

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.05201818 0.0879348 -0.0005421 0.00046309] +- [0.00107396 0.00247638 0.00008235 0.00005965]

projection: [1030.65992481 1030.382989 640.06913196 360.93521474] +- [0.16300075 0.16067049 0.01269783 0.1347229]

reprojection error: [-0.000155, 0.000139] +- [0.525809, 0.460925]

cam1 (/prophesee/right/events):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.05529555 0.08241079 0.00012524 0.00101529] +- [0.00106393 0.00237797 0.00007464 0.0000585]

projection: [1030.09042286 1029.73030511 640.15930521 360.65834854] +- [0.1769099 0.17055204 0.00623406 0.08099238]

reprojection error: [-0.000132, 0.000351] +- [0.727134, 0.599162]

cam2 (/ovc/left/image_mono/compressed):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.3926429 0.15629572 0.00081903 0.00033549] +- [0.00051509 0.00085261 0.00005983 0.00003716]

projection: [1055.47437867 1056.11872168 679.53598529 327.77957782] +- [0.14009439 0.14133937 0.01122238 0.23568603]

reprojection error: [-0.000067, 0.000599] +- [0.205932, 0.192997]

cam3 (/ovc/right/image_mono/compressed):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.38786303 0.14533473 0.00039012 0.00091234] +- [0.00041011 0.00056997 0.00005319 0.00003448]

projection: [1049.87045895 1050.70633008 673.9759719 323.03165232] +- [0.14177621 0.13994827 0.00889258 0.23065705]

reprojection error: [0.000188, 0.000378] +- [0.233078, 0.198265]

cam4 (/ovc/rgb/image_color/compressed):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.41571279 0.18693884 0.00100019 -0.00016628] +- [0.00074987 0.0017483 0.00006139 0.00003986]

projection: [1261.99912824 1262.31385289 654.21725293 359.66142806] +- [0.15676452 0.15420608 0.00600245 0.08330613]

reprojection error: [0.000179, 0.000440] +- [0.220763, 0.204945]

baseline T_1_0:

q: [-0.00006018 0.00154694 -0.00005475 0.9999988] +- [0.00009947 0.00007353 0.000043]

t: [-0.12017726 0.00103186 -0.00049839] +- [0.00004075 0.00003655 0.0001327]

baseline T_2_1:

q: [0.0004752 -0.00239864 -0.00542506 0.99998229] +- [0.00026549 0.00006579 0.00004017]

t: [0.12002391 0.06901675 0.00388781] +- [0.00003748 0.00003459 0.00012309]

baseline T_3_2:

q: [-0.00094464 -0.00377673 0.00052297 0.99999229] +- [0.00032522 0.00005486 0.00003521]

t: [-0.11992907 -0.00010809 0.00073673] +- [0.00003216 0.0000318 0.00010759]

baseline T_4_3:

q: [0.00231292 0.00462794 0.00021225 0.99998659] +- [0.00026358 0.00005213 0.00003548]

t: [0.08873341 0.00622195 0.00357433] +- [0.00003141 0.0000295 0.00010807]

Target configuration

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Type: aprilgrid

Tags:

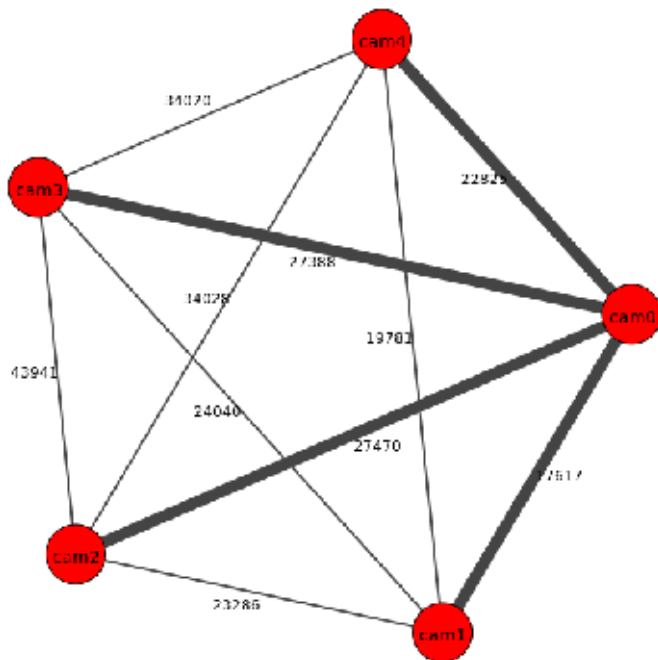
Rows: 5

Cols: 7

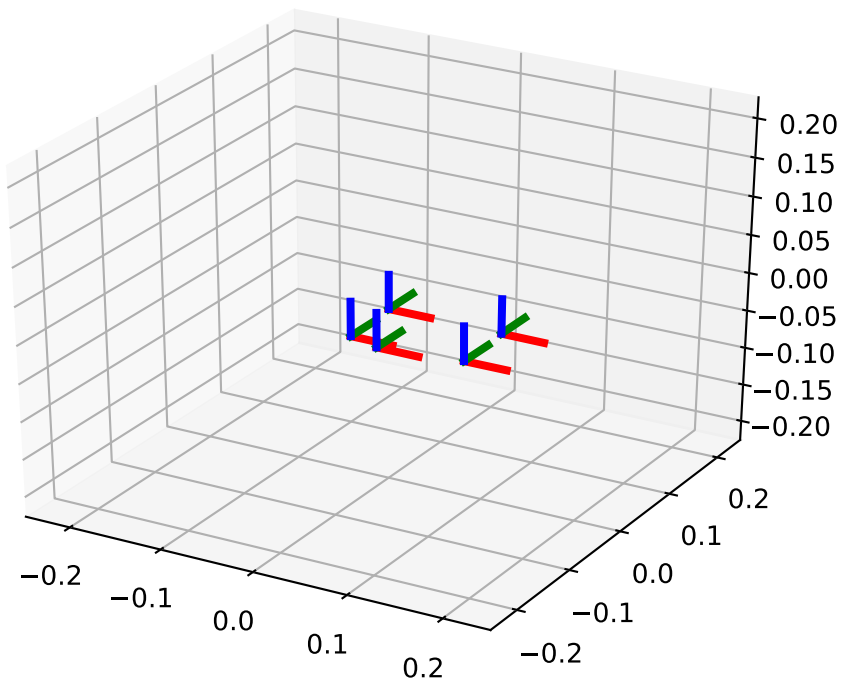
Size: 0.04 [m]

Spacing 0.01 [m]

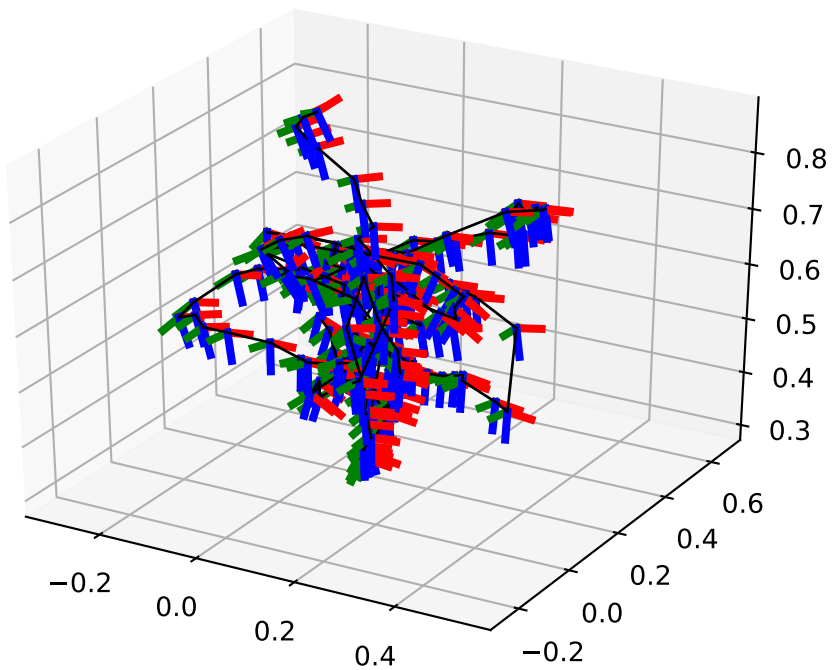
Inter-camera observations graph (edge weight=#mutual obs.)



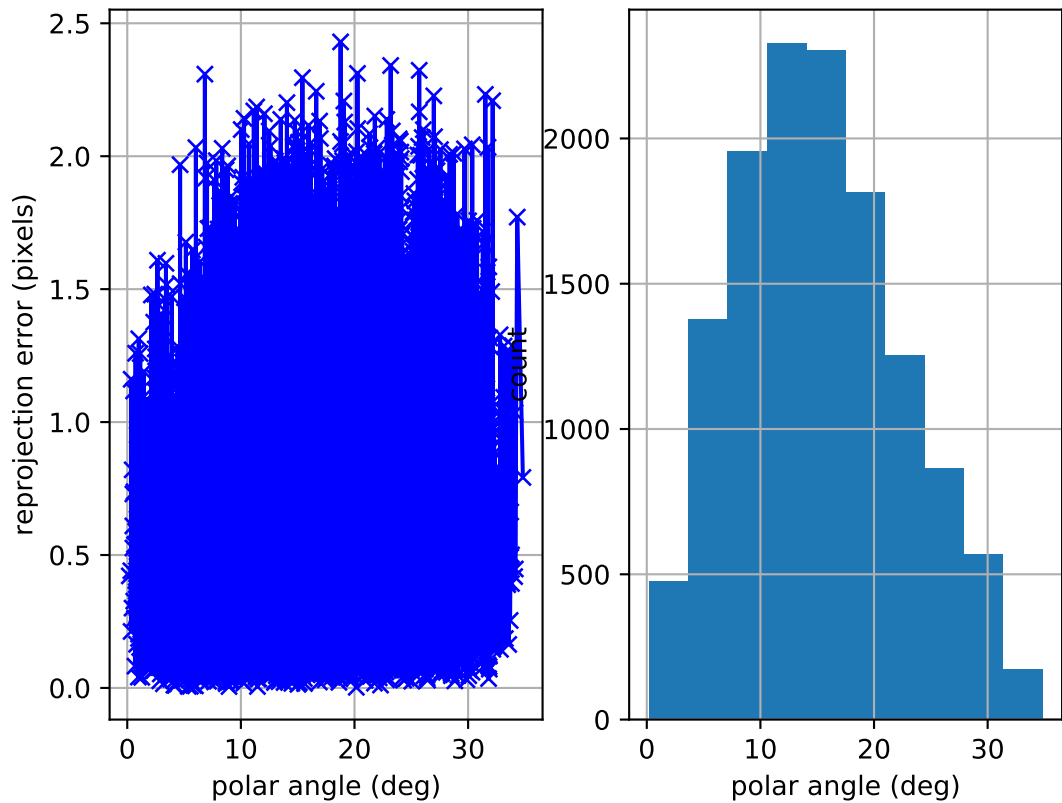
camera system



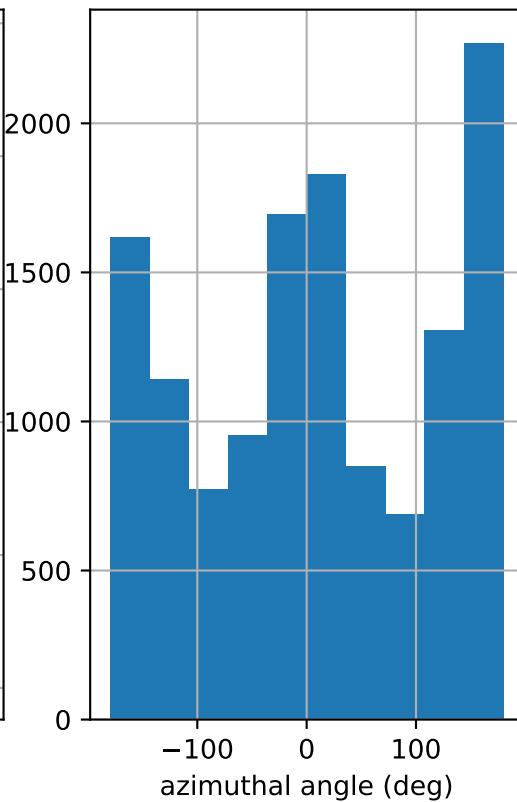
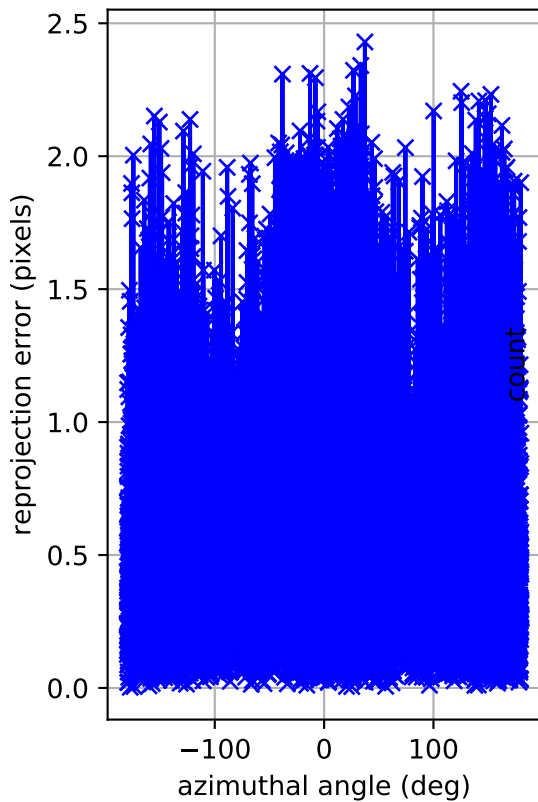
cam0: estimated poses



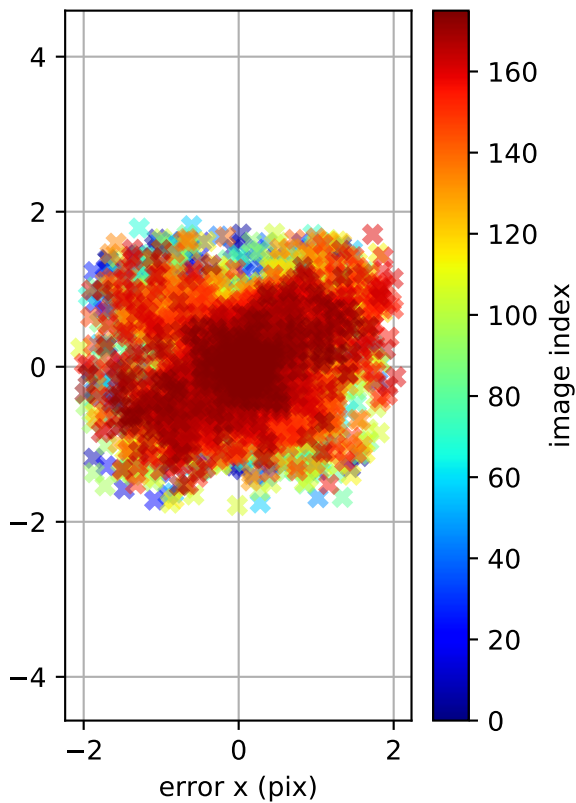
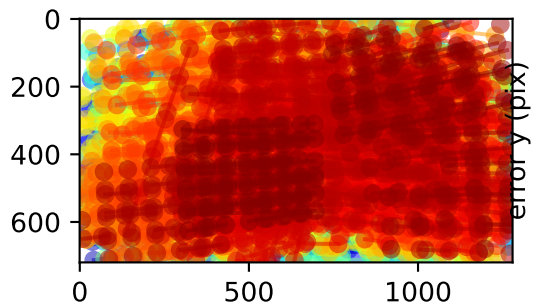
cam0: polar error



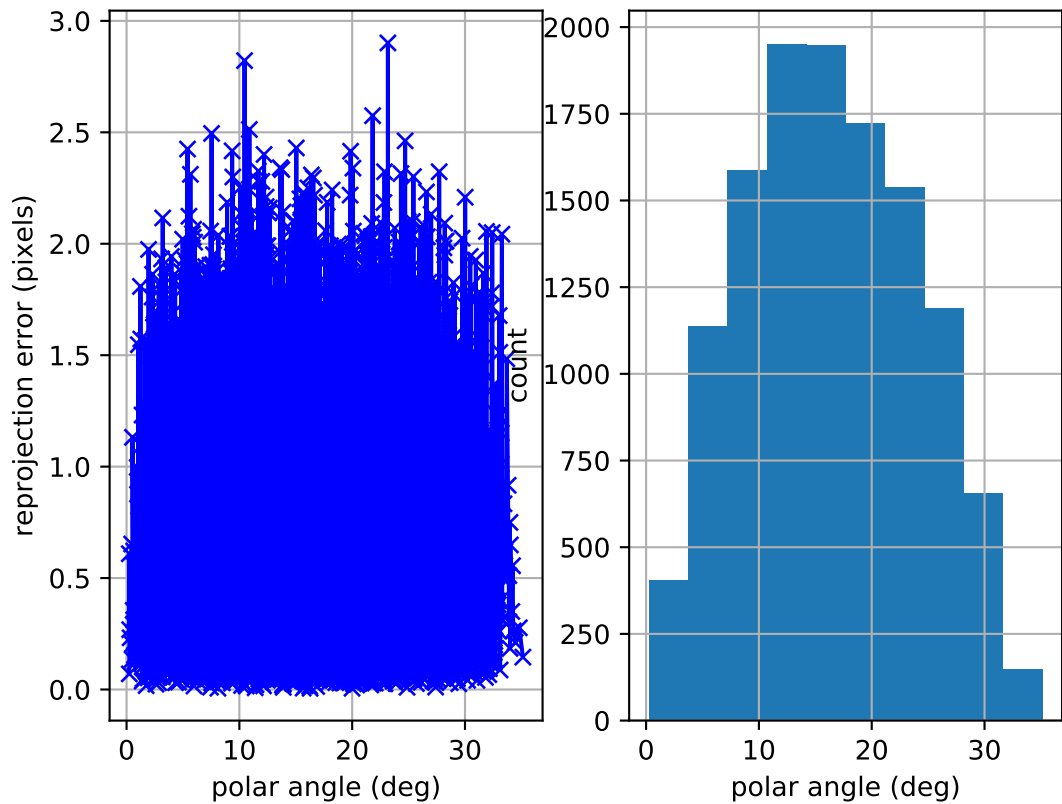
cam0: azimuthal error



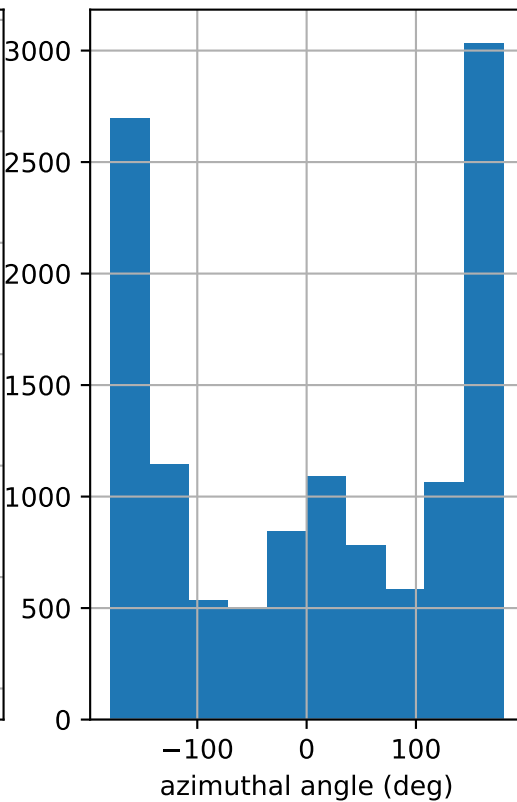
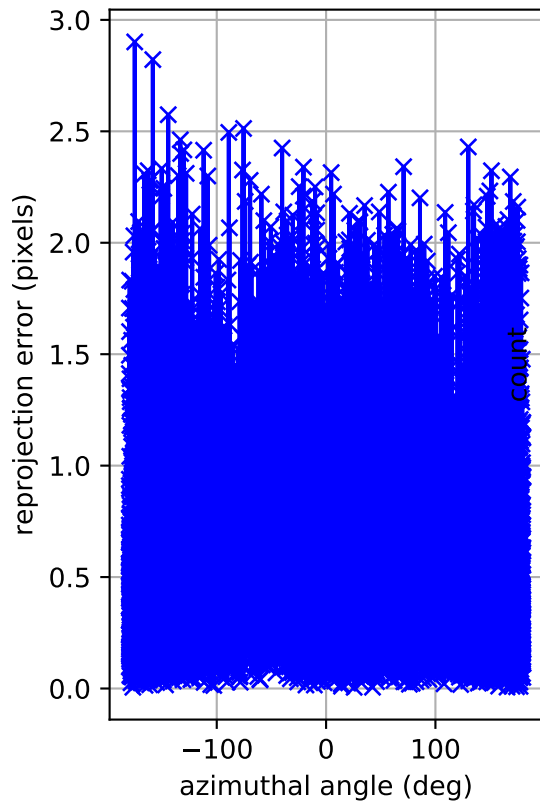
cam0: reprojection errors



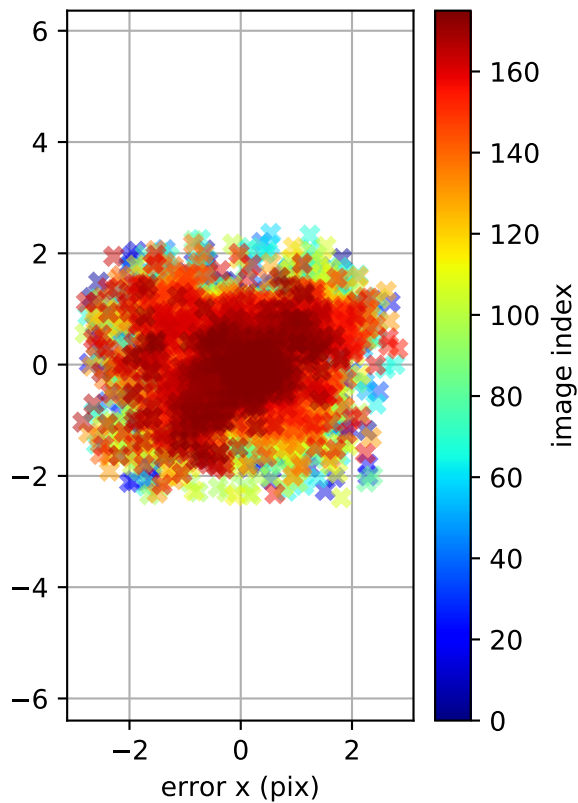
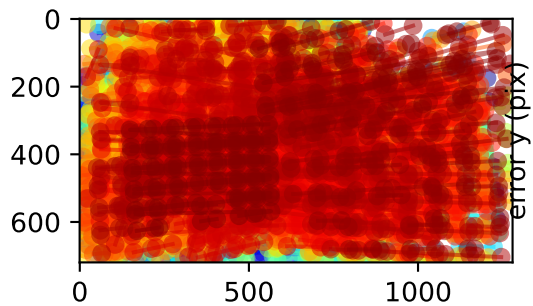
cam1: polar error



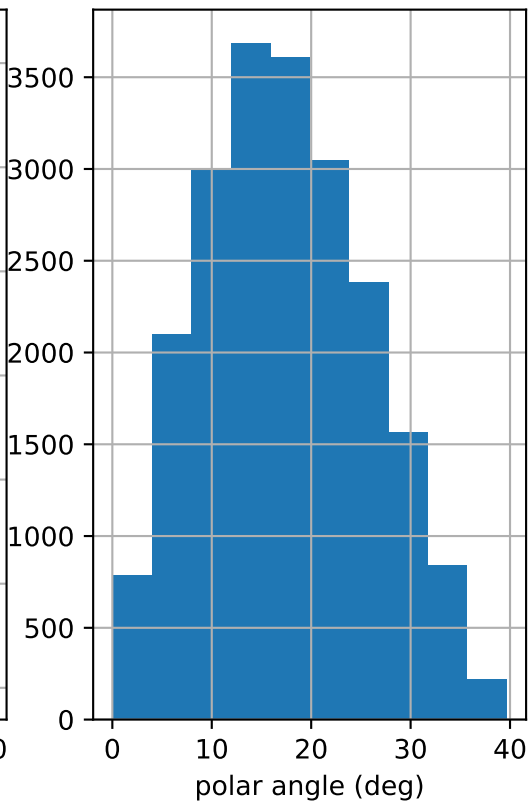
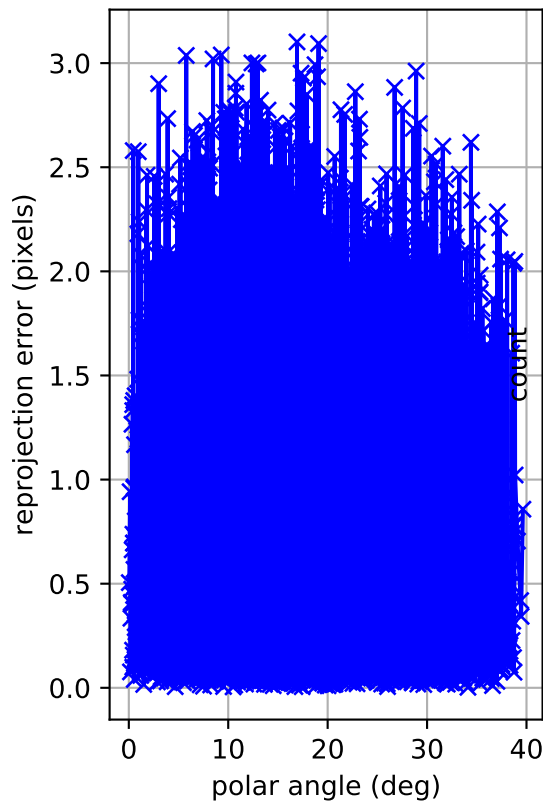
cam1: azimuthal error



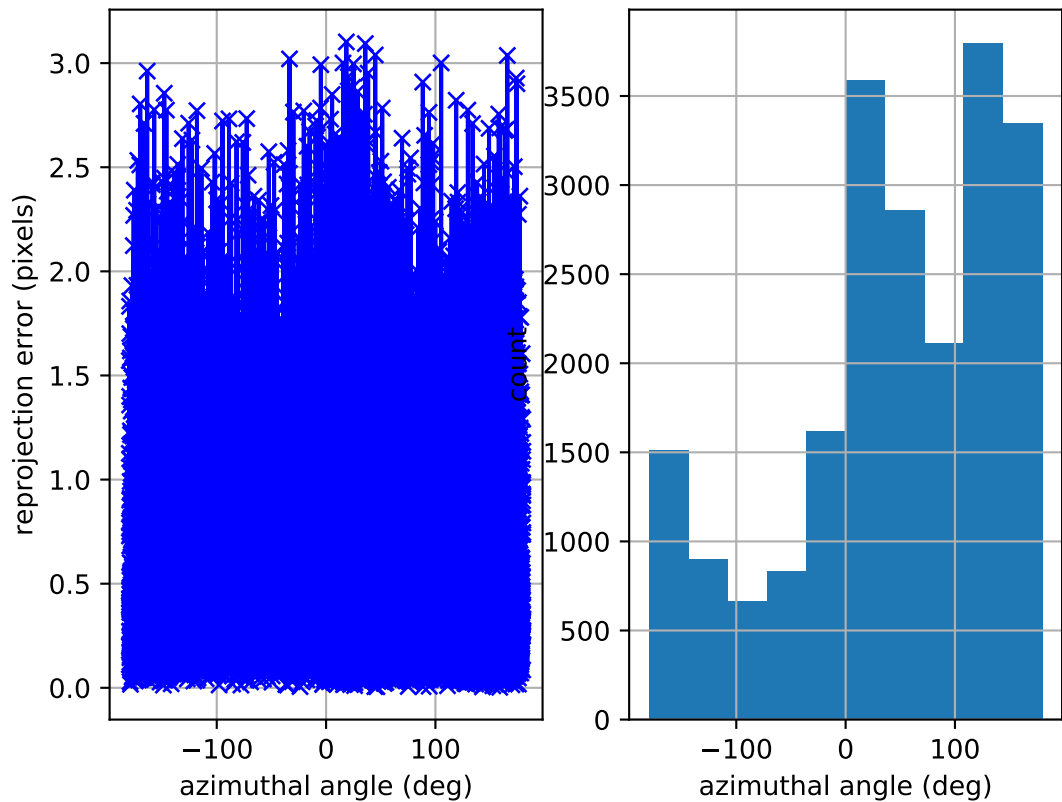
cam1: reprojection errors



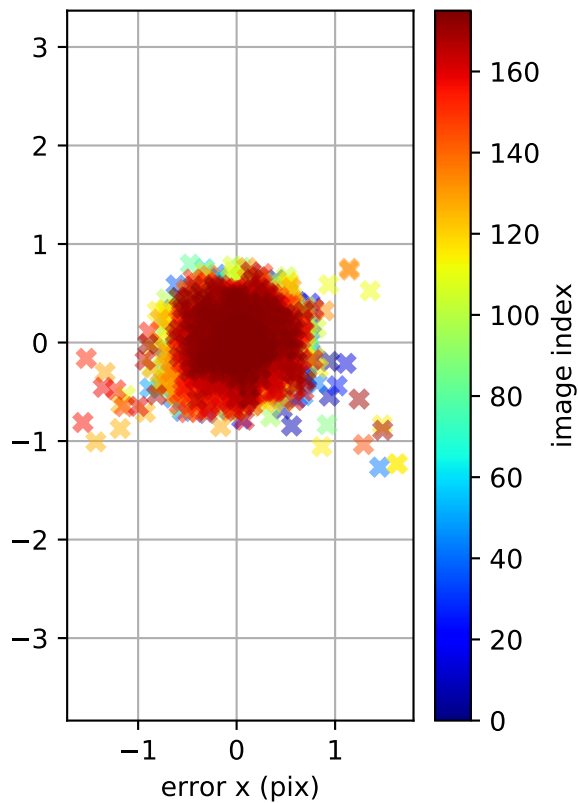
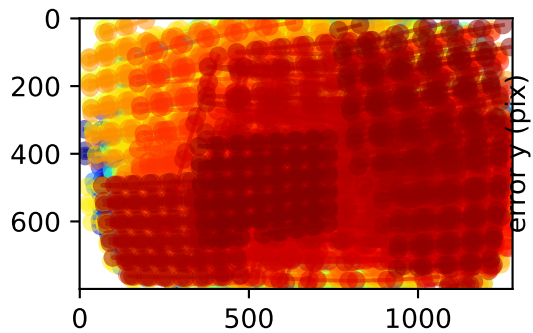
cam2: polar error



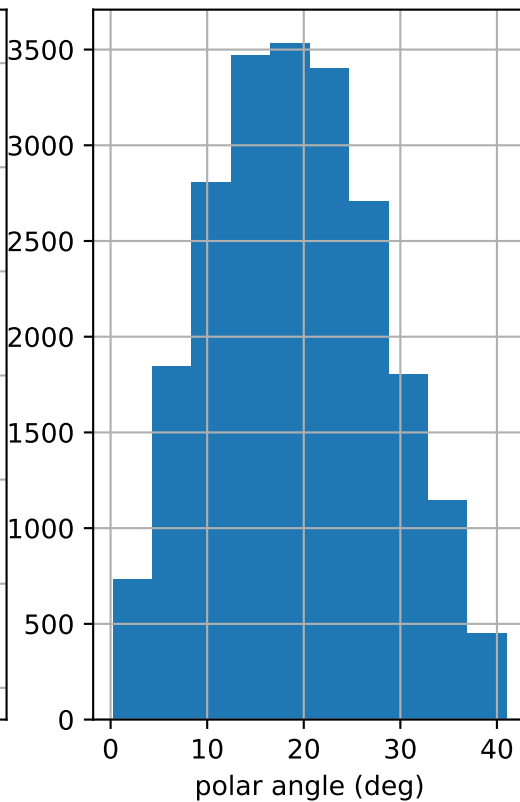
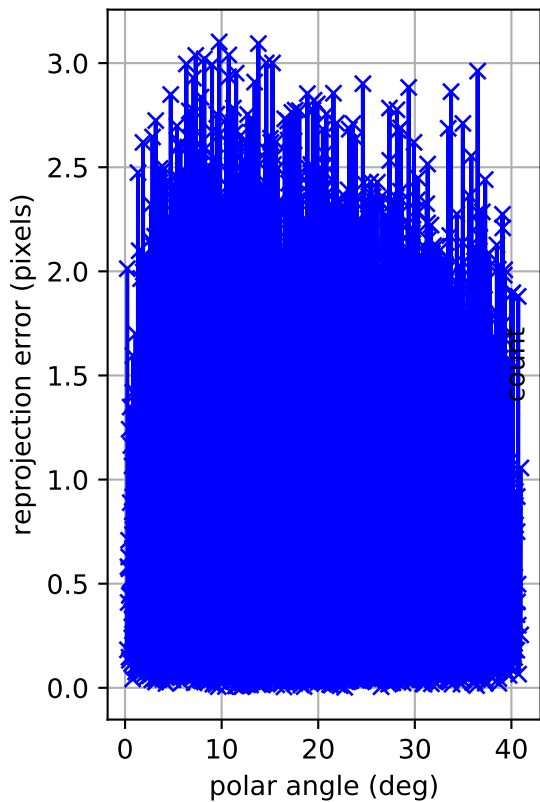
cam2: azimuthal error



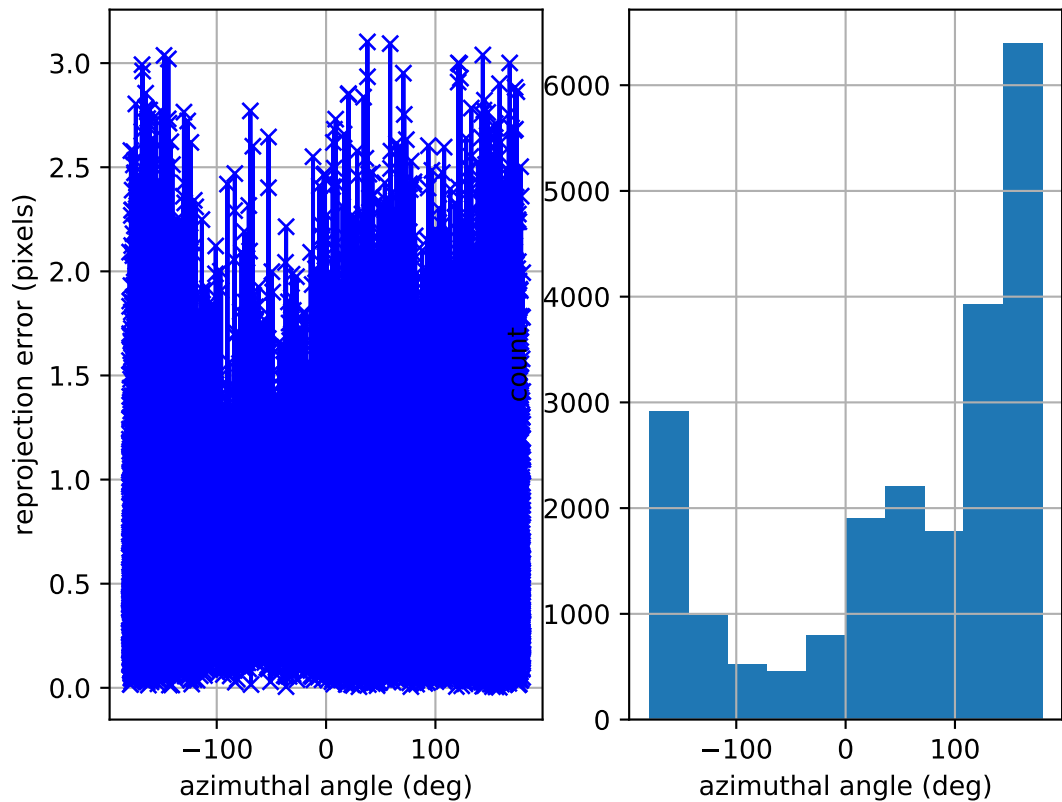
cam2: reprojection errors



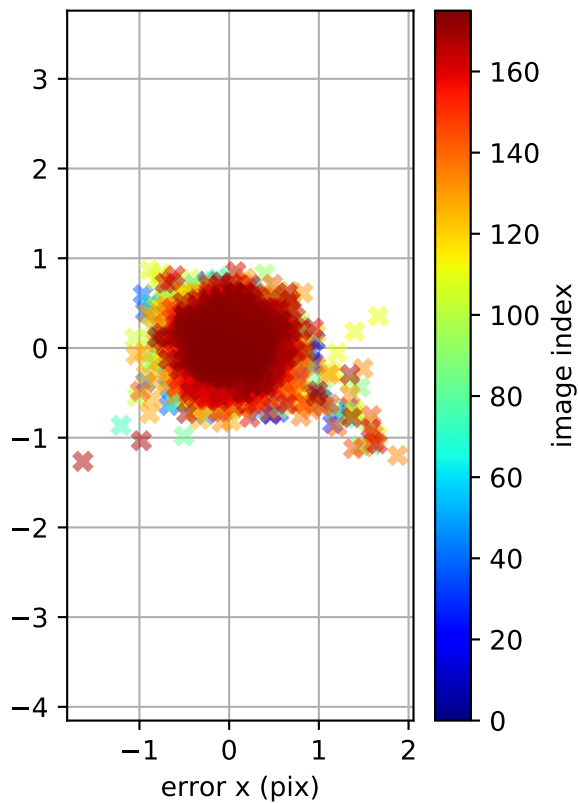
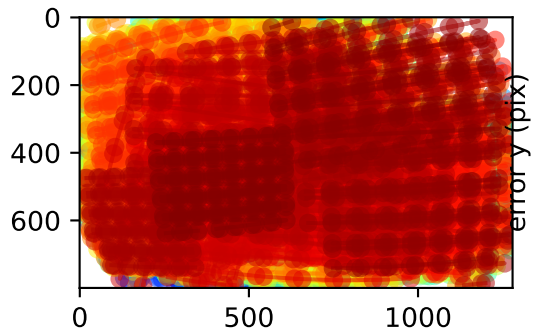
cam3: polar error



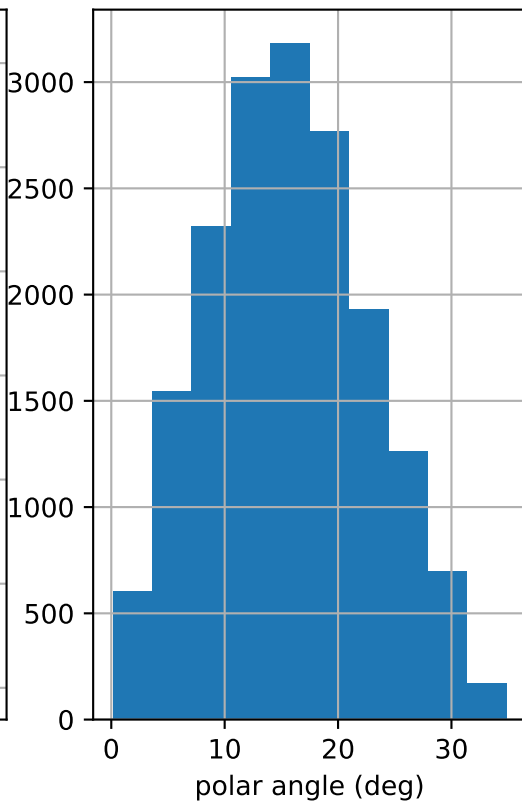
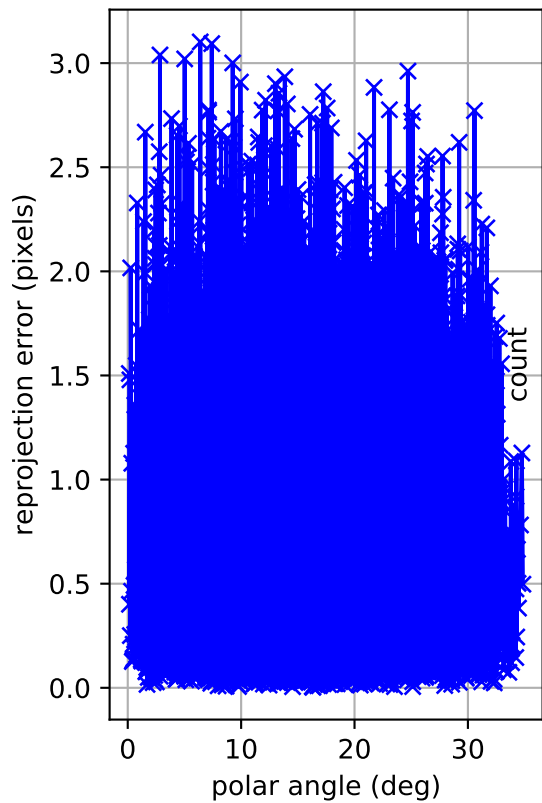
cam3: azimuthal error



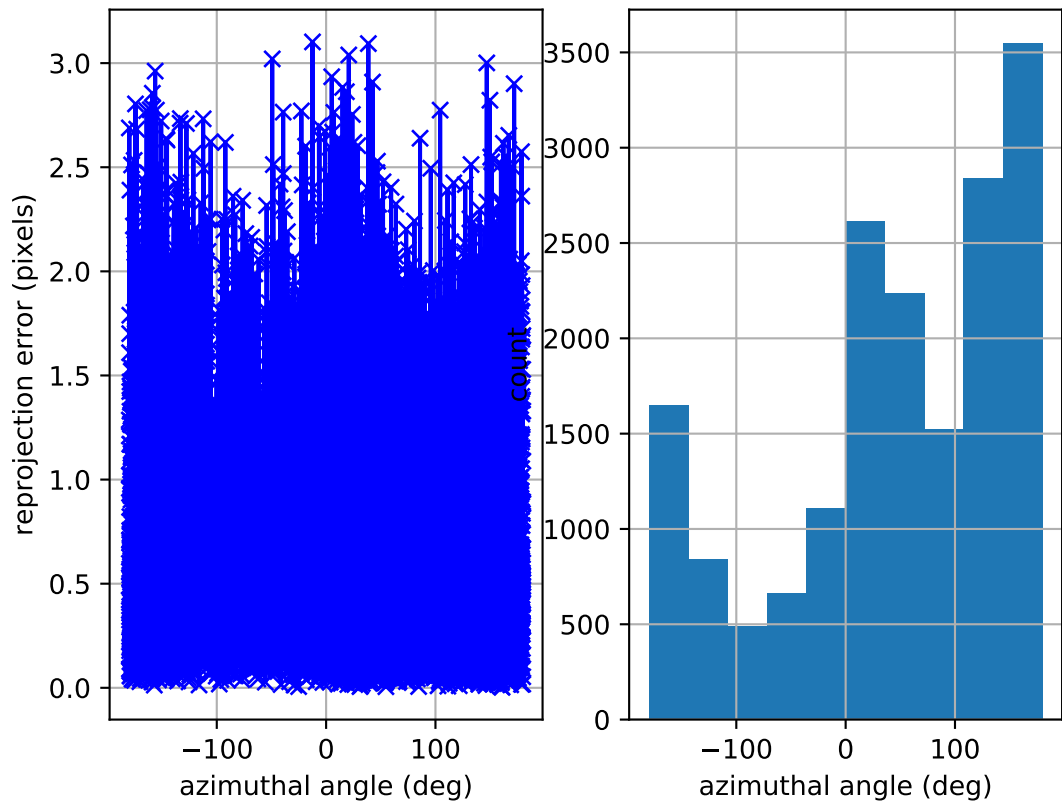
cam3: reprojection errors



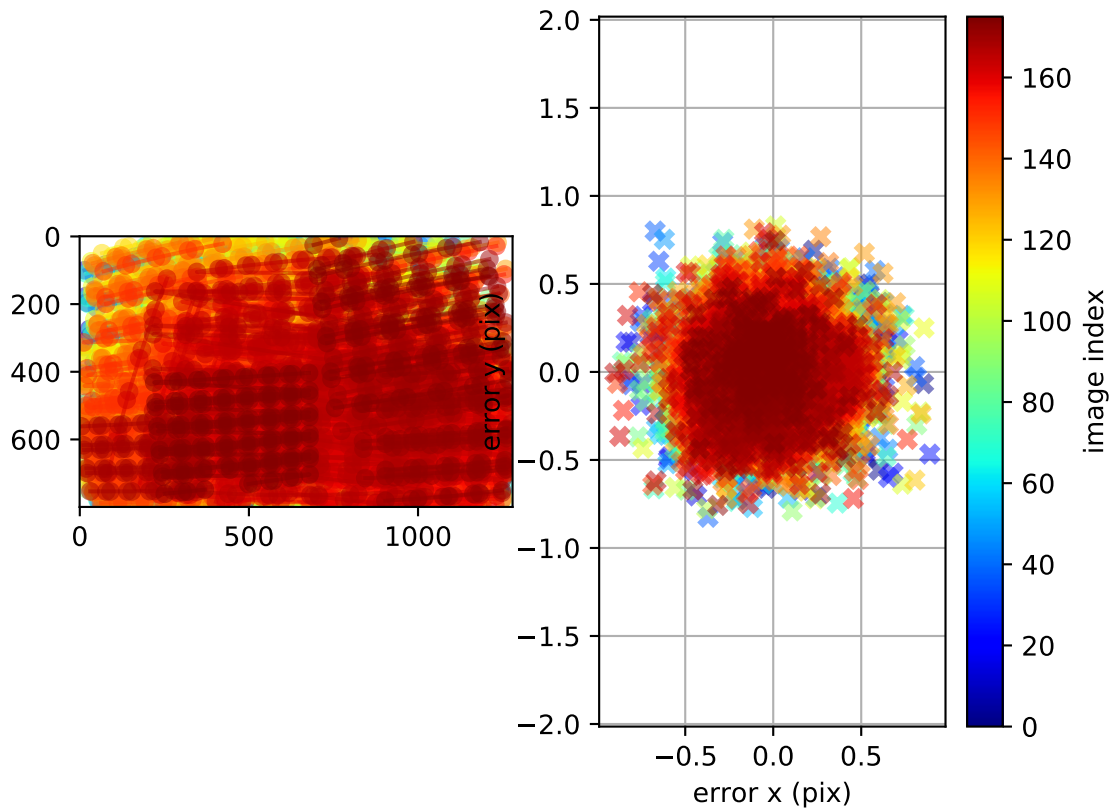
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

