

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04710825 0.07750951 0.00043356 0.0001561] +- [0.00087418 0.00185027 0.00007145 0.00005105]
projection: [1028.20896453 1027.8915324 638.06460891 365.72680984] +- [0.11861728 0.11948496 0.00731092
0.10137203]

reprojection error: [-0.000126, -0.000291] +- [0.584431, 0.575669]

cam1 (/prophesee/right/events):

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

distortion: [-0.05257437 0.07959145 0.00143033 0.00109985] +- [0.00090041 0.00192354 0.00007216 0.0000573]
projection: [1027.87122428 1027.72913779 639.65045941 366.49531604] +- [0.12641775 0.12500304 0.00503287
0.09642822]

reprojection error: [-0.000034, -0.000108] +- [0.614993, 0.583058]

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

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

distortion: [-0.38691592 0.14807492 -0.00001491 0.00059266] +- [0.00043243 0.00068103 0.00004892 0.00003143]
projection: [1052.8809339 1053.04595506 675.65951484 333.93238258] +- [0.10589833 0.10804934 0.00698084
0.17087732]

reprojection error: [0.000168, 0.000259] +- [0.285899, 0.249505]

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

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

distortion: [-0.38664178 0.14470425 -0.00039765 0.00104969] +- [0.00038558 0.00055229 0.00004686 0.0000351]
projection: [1048.22036373 1048.664011 672.88491581 328.14924327] +- [0.10714738 0.10740881 0.00507909
0.16565899]

reprojection error: [0.000374, 0.000084] +- [0.284906, 0.248143]

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

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

distortion: [-0.41111721 0.18022438 -0.00013261 0.00016641] +- [0.00068658 0.00157093 0.00005239 0.00003588]
projection: [1259.6905929 1259.56535186 651.57533264 367.8103925] +- [0.12074755 0.12116242 0.00350129
0.03569351]

reprojection error: [0.000429, -0.000222] +- [0.327104, 0.354205]

baseline T_1_0:

q: [-0.00072729 0.00224701 -0.00030287 0.99999717] +- [0.00006916 0.00004775 0.00003396]

t: [-0.12018171 0.00096641 -0.0003373] +- [0.00003007 0.00002711 0.00009106]

baseline T_2_1:

q: [0.00009999 -0.00401417 -0.00528302 0.99997798] +- [0.0002254 0.00004478 0.00003169]

t: [0.12006212 0.06954627 0.00359061] +- [0.00002868 0.00002664 0.00008979]

baseline T_3_2:

q: [-0.000535 -0.00243525 0.00032461 0.99999684] +- [0.00024995 0.00004126 0.00002804]

t: [-0.11996006 -0.00007587 0.00103551] +- [0.00002691 0.00002417 0.00008321]

baseline T_4_3:

q: [0.00145697 0.00415648 0.00034121 0.99999024] +- [0.00018011 0.00003834 0.00002747]

t: [0.08885877 0.00625581 0.00347604] +- [0.0000247 0.00002341 0.0000835]

Target configuration

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Type: aprilgrid

Tags:

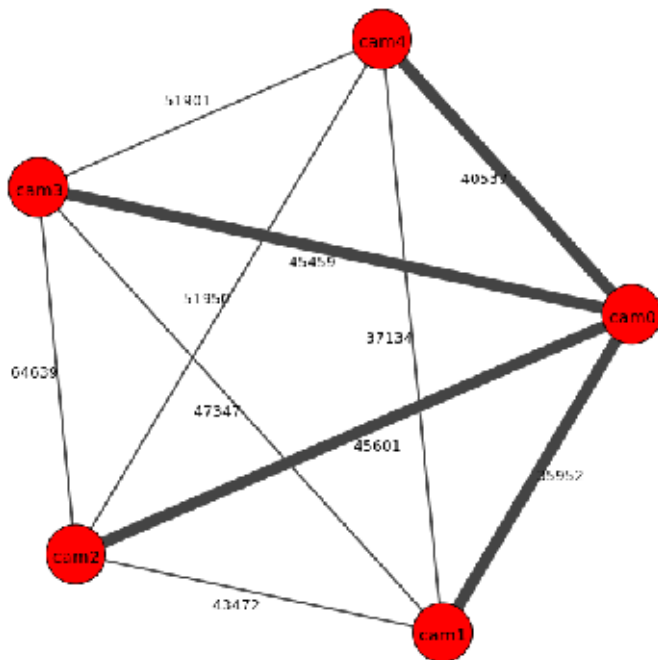
Rows: 5

Cols: 7

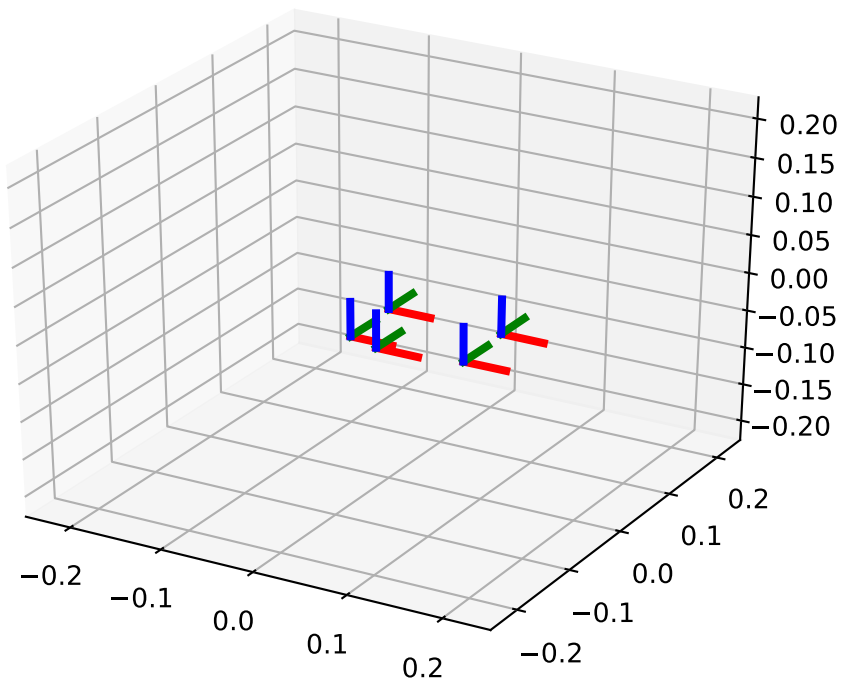
Size: 0.04 [m]

Spacing 0.01 [m]

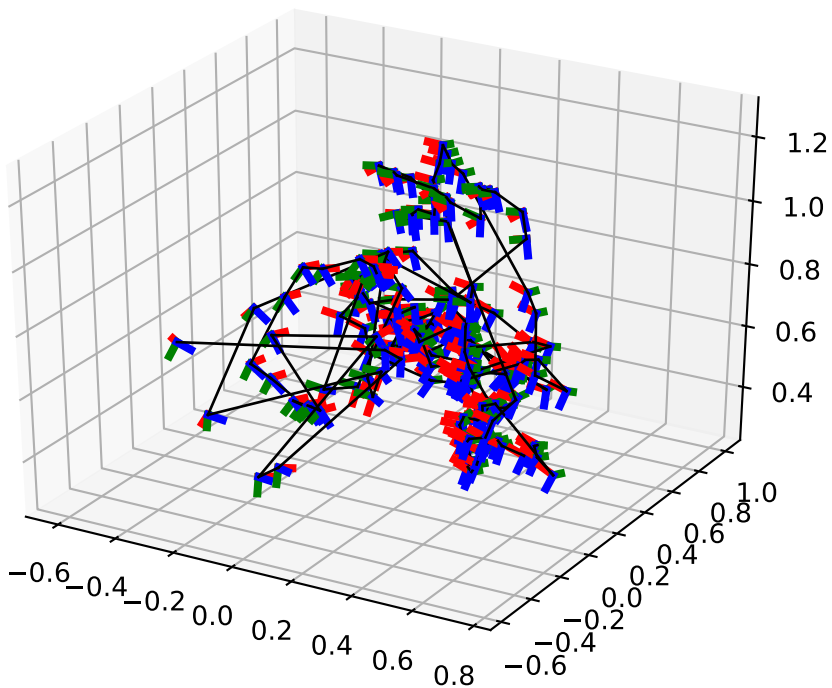
Inter-camera observations graph (edge weight=#mutual obs.)



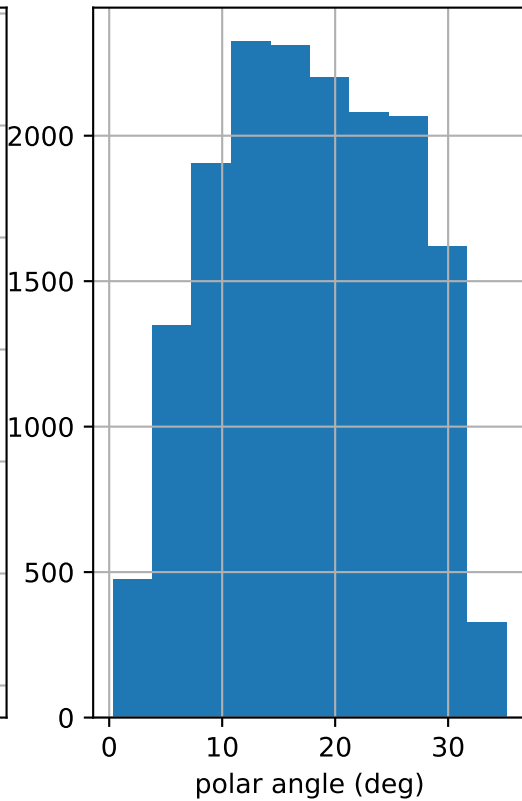
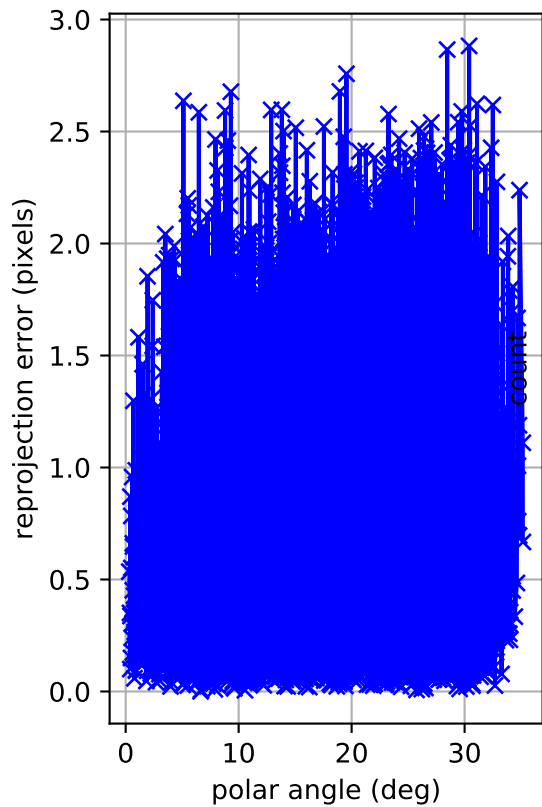
camera system



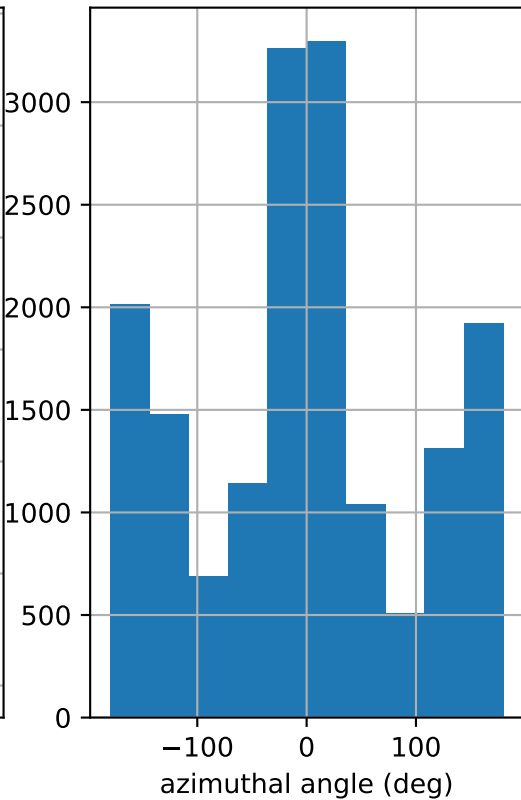
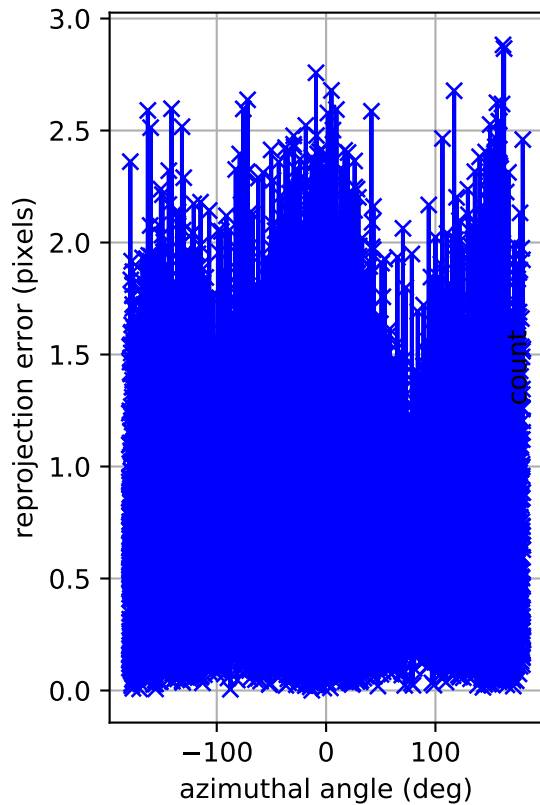
cam0: estimated poses



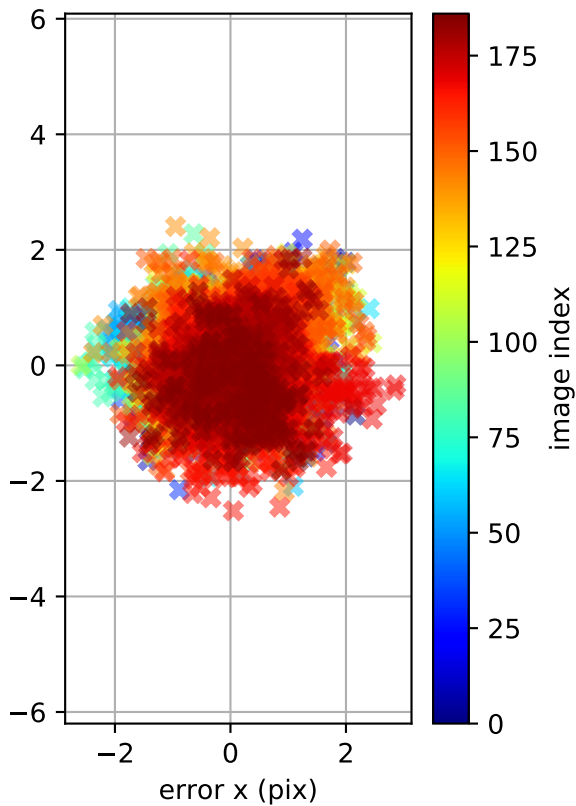
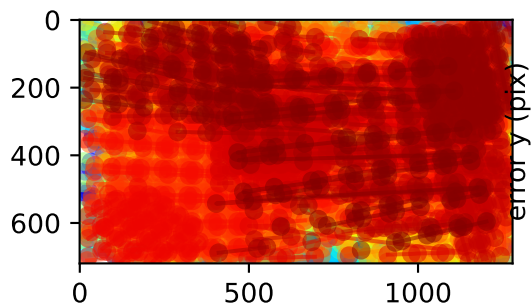
cam0: polar error



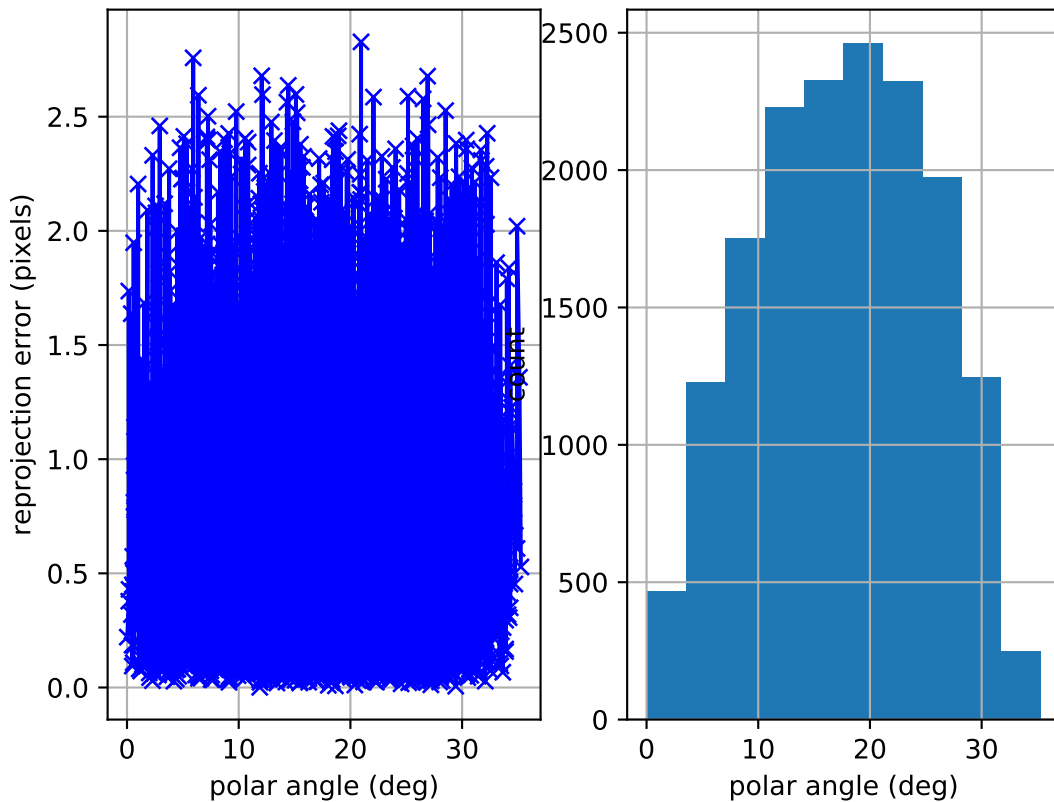
cam0: azimuthal error



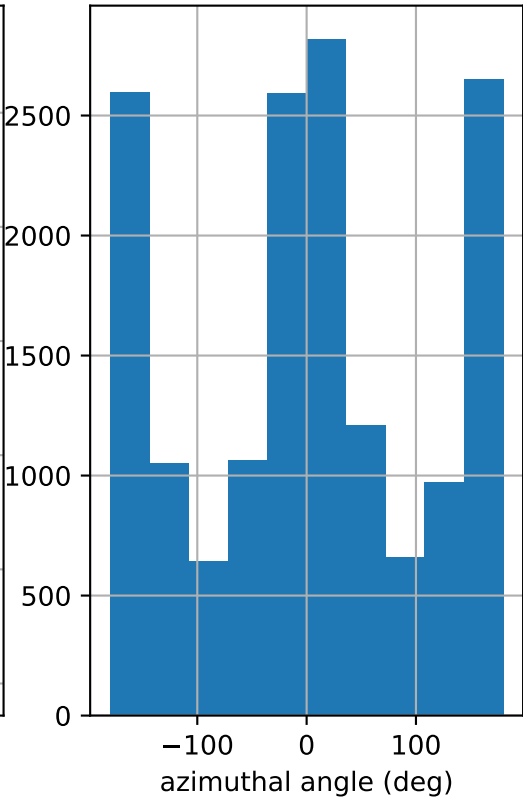
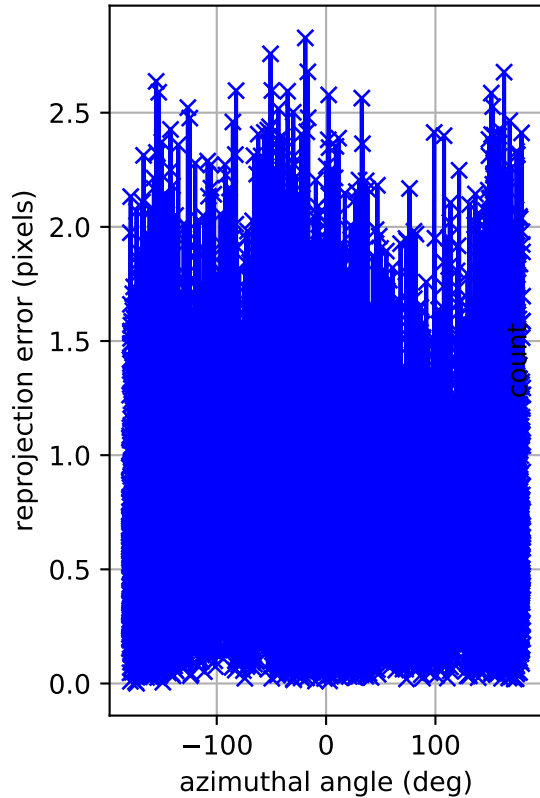
cam0: reprojection errors



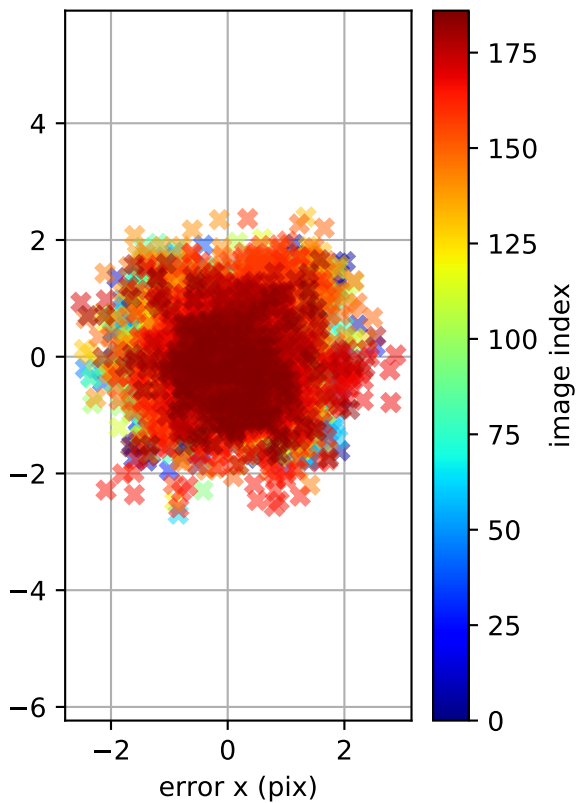
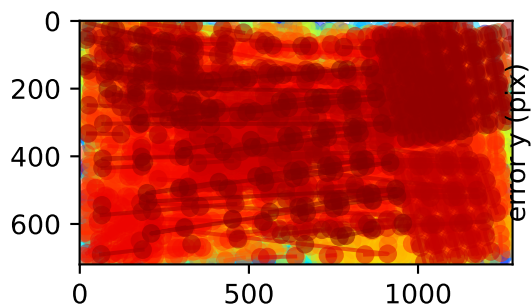
cam1: polar error



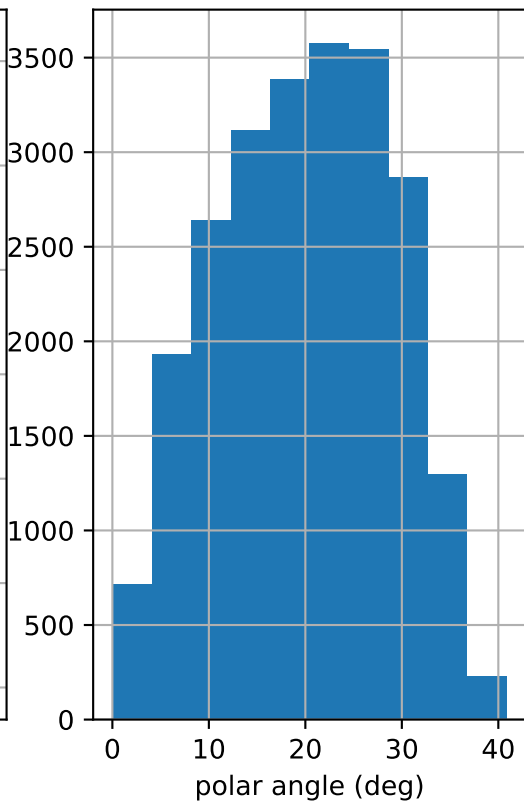
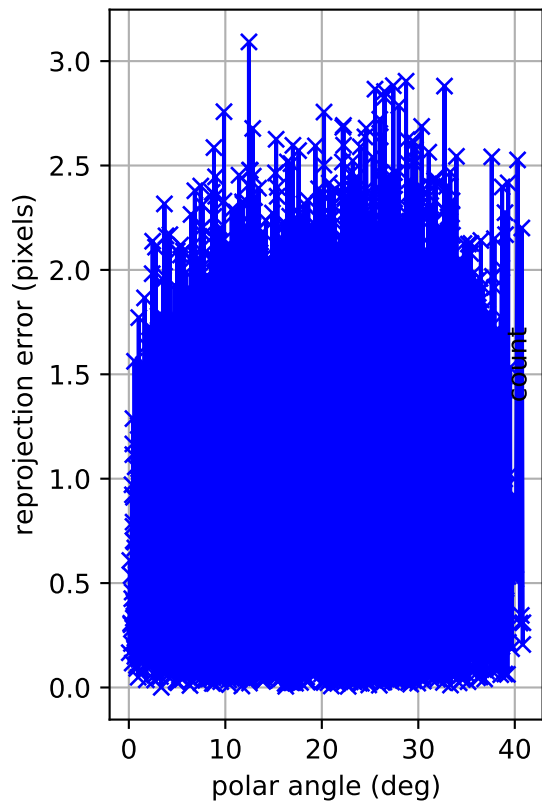
cam1: azimuthal error



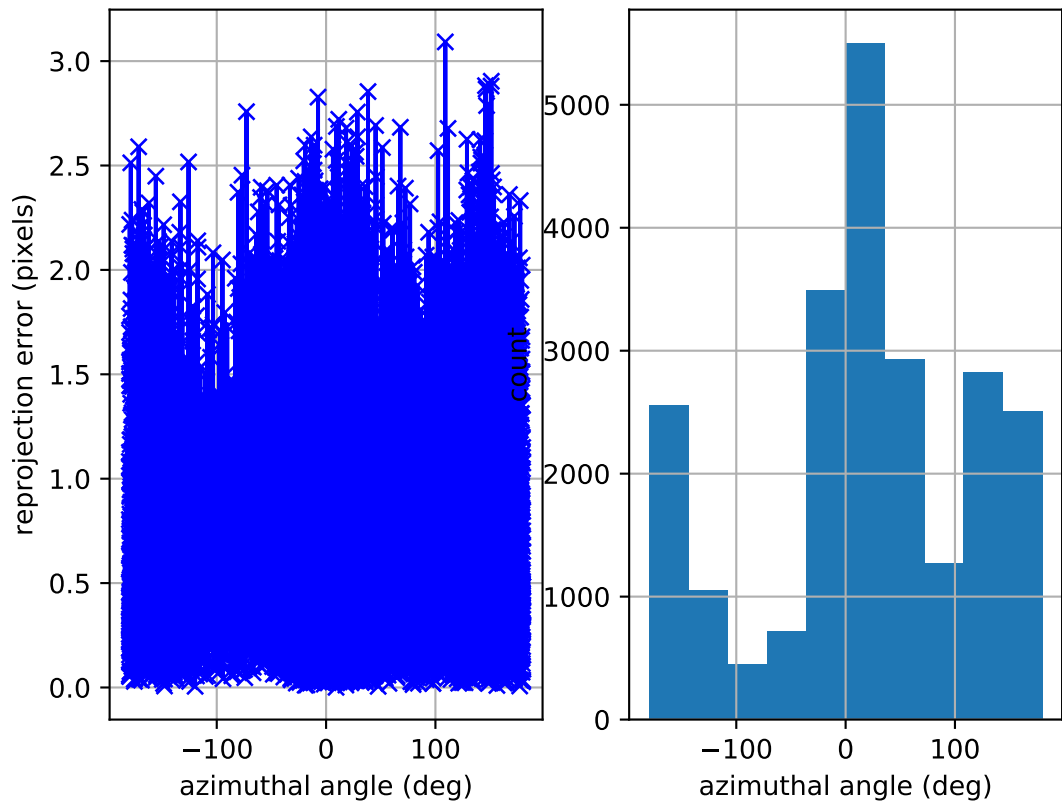
cam1: reprojection errors



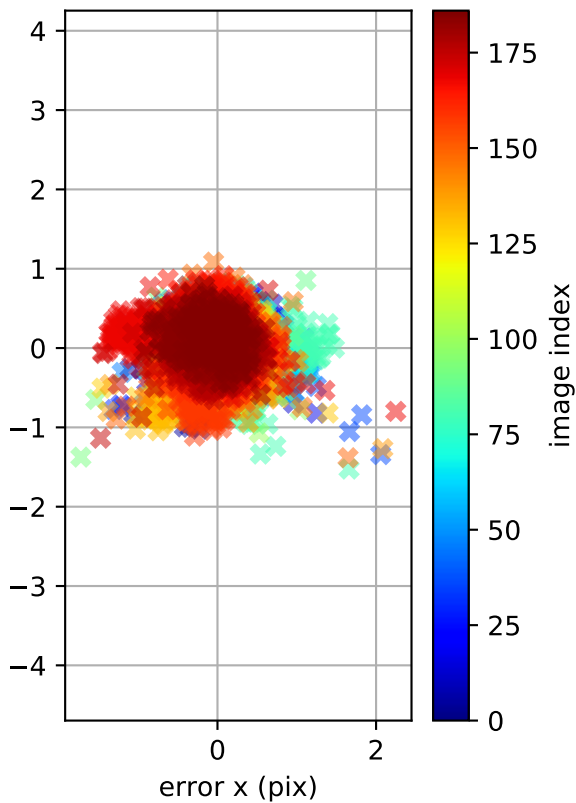
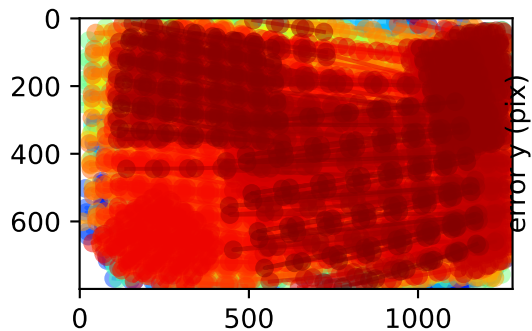
cam2: polar error



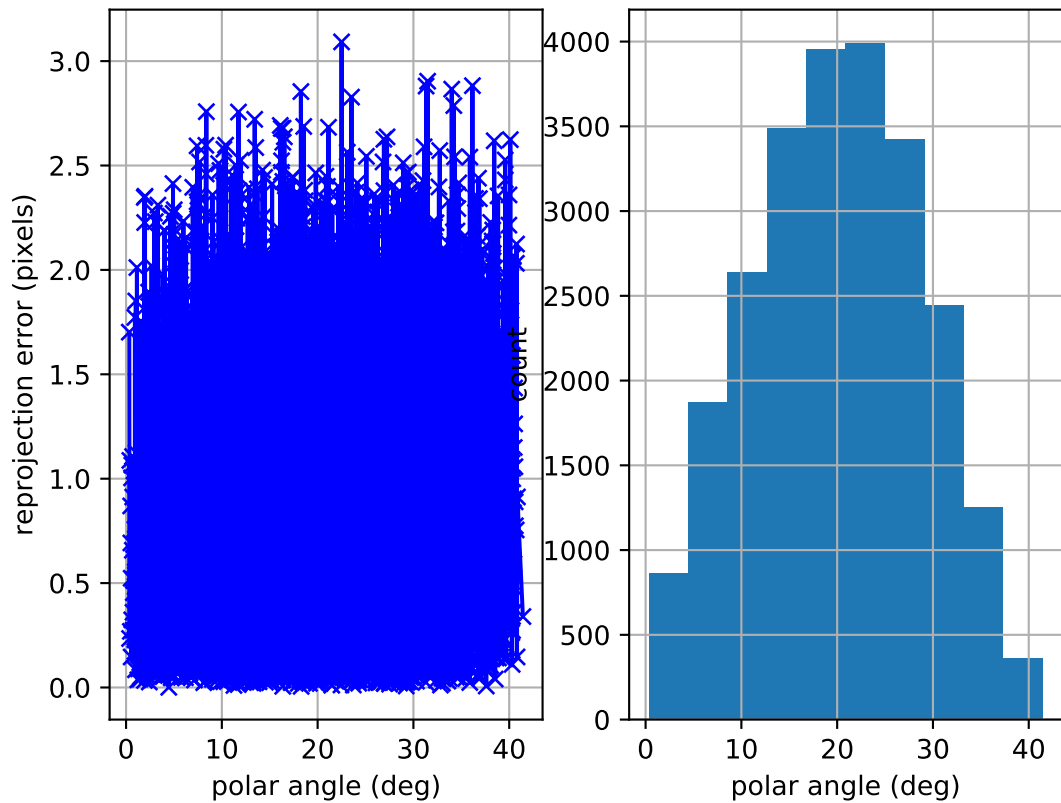
cam2: azimuthal error



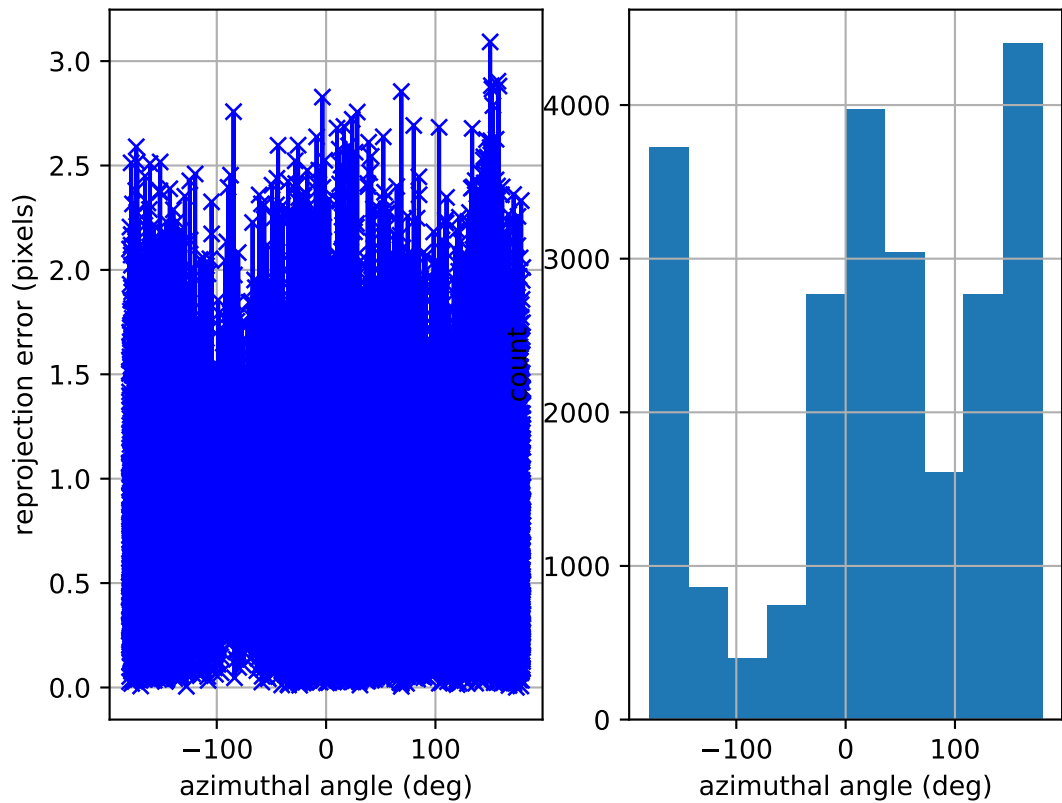
cam2: reprojection errors



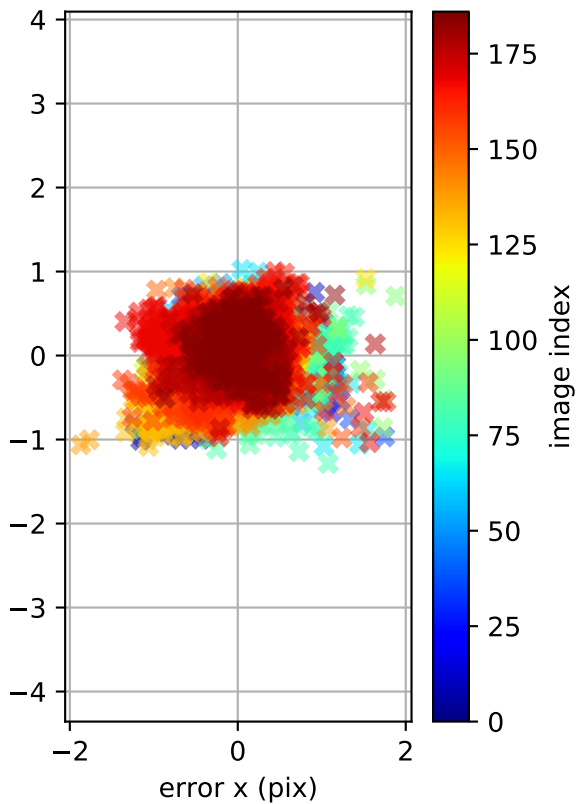
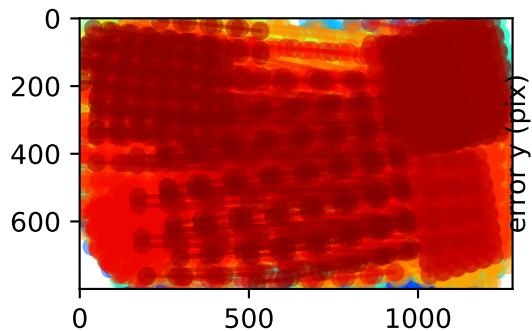
cam3: polar error



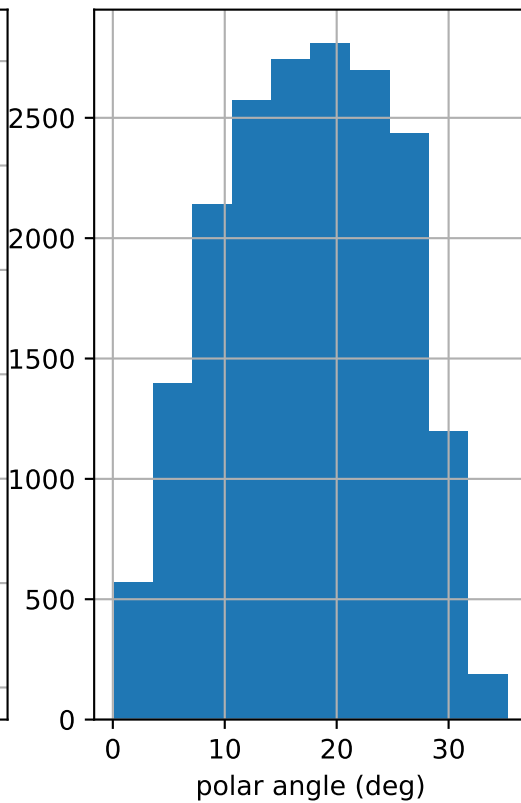
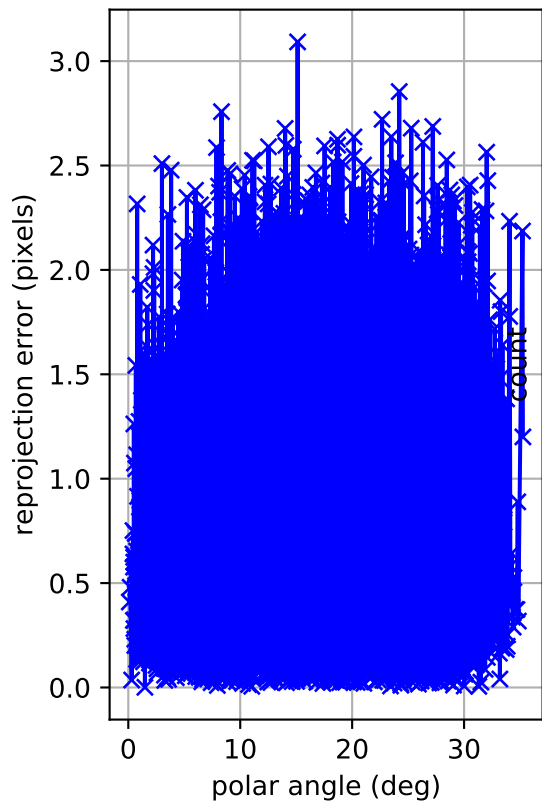
cam3: azimuthal error



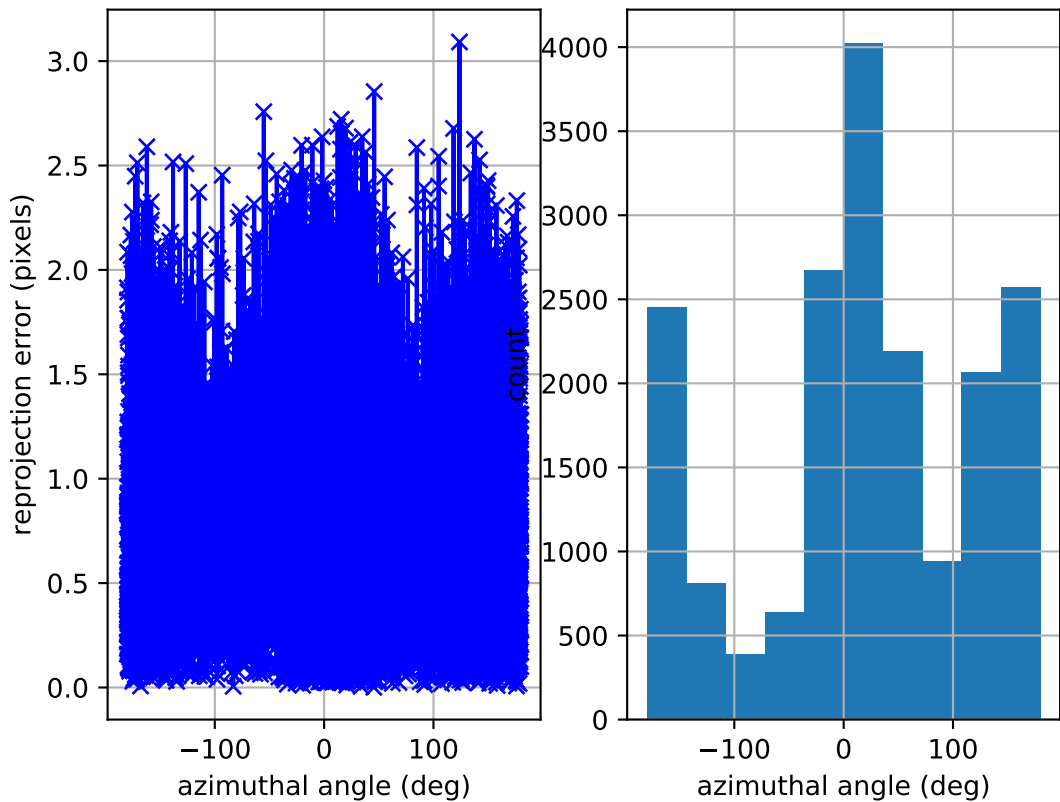
cam3: reprojection errors



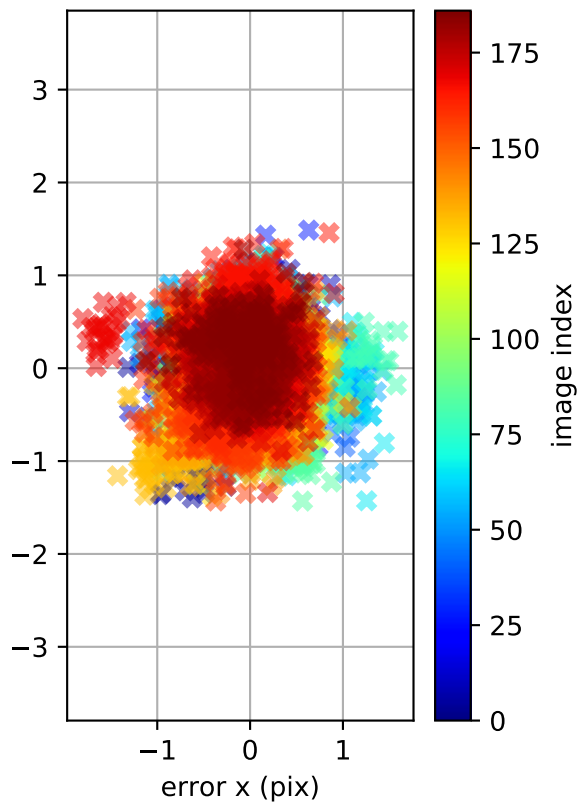
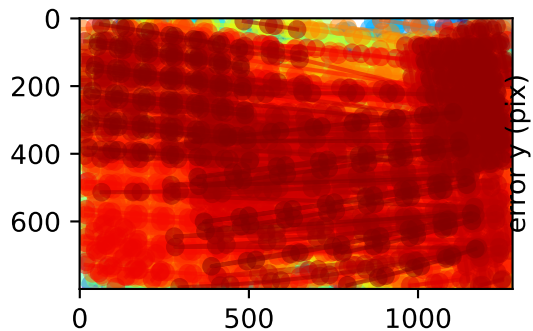
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

