

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04805022 0.0505056 -0.0020204 -0.01057718] +- [0.0007831 0.00151549 0.00006763 0.00005327]
projection: [1032.3690086 1026.33175765 599.13004363 360.0675969] +- [0.14178235 0.1409297 0.01061725 0.10815924]

reprojection error: [-0.000324, 0.000332] +- [5.096748, 2.880047]

cam1 (/prophesee/right/events):

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

distortion: [-0.05619684 0.07304762 0.00010565 -0.00861453] +- [0.00091162 0.00196793 0.00007198 0.0000542]
projection: [1028.96402904 1025.0555768 612.43354214 362.6059749] +- [0.14650804 0.14434894 0.01346854 0.09952207]

reprojection error: [-0.000652, 0.000564] +- [5.134071, 2.707884]

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

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

distortion: [-0.38017872 0.13324396 0.00042345 -0.00054668] +- [0.00036702 0.00052553 0.00004674 0.00002892]
projection: [1050.15390984 1050.82480534 683.00014075 336.97476652] +- [0.12238467 0.12294942 0.01460388 0.1889909]

reprojection error: [-0.000475, 0.000578] +- [2.462683, 1.269313]

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

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

distortion: [-0.38002667 0.13149355 -0.00007706 -0.00023448] +- [0.00031399 0.00040278 0.00004592 0.00003163]
projection: [1045.08881749 1046.32443518 681.31040024 328.78453597] +- [0.11570041 0.11760263 0.01087547 0.18558129]

reprojection error: [-0.000271, 0.000567] +- [2.327337, 1.222977]

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

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

distortion: [-0.4088645 0.17354526 0.00111334 -0.00096761] +- [0.00071886 0.00172227 0.00005161 0.00003587]
projection: [1256.29668257 1256.83540978 658.04653963 364.27319482] +- [0.13864405 0.13743415 0.00640349 0.05781385]

reprojection error: [-0.000228, 0.000622] +- [2.625179, 1.323668]

baseline T_1_0:

q: [-0.00124634 0.00749074 0.00034909 0.99997111] +- [0.00008732 0.00006557 0.00003982]

t: [-0.12022182 0.00056433 0.00119947] +- [0.00003532 0.00003279 0.00010855]

baseline T_2_1:

q: [-0.00449177 0.01207054 -0.00436622 0.99990753] +- [0.00025139 0.00006108 0.00003613]

t: [0.11861345 0.07031882 0.00462853] +- [0.00003224 0.00003185 0.00010302]

baseline T_3_2:

q: [0.00059374 -0.00239057 0.00018818 0.99999695] +- [0.00026369 0.00005216 0.00002991]

t: [-0.12011082 -0.00002634 0.00042886] +- [0.00002929 0.00002806 0.00009192]

baseline T_4_3:

q: [0.00330618 0.00326183 0.00024823 0.99998918] +- [0.00021167 0.00004763 0.00003083]

t: [0.08917737 0.00616217 0.00343995] +- [0.00002812 0.00002785 0.0000946]

Target configuration

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Type: aprilgrid

Tags:

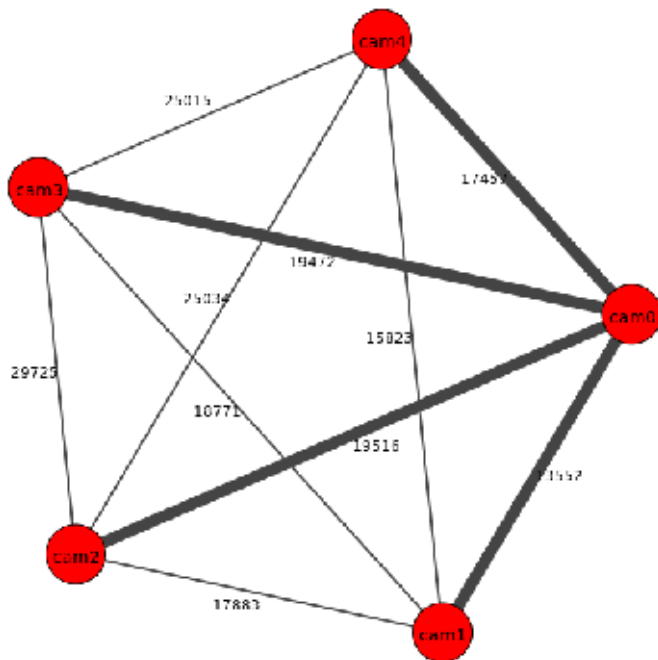
Rows: 5

Cols: 7

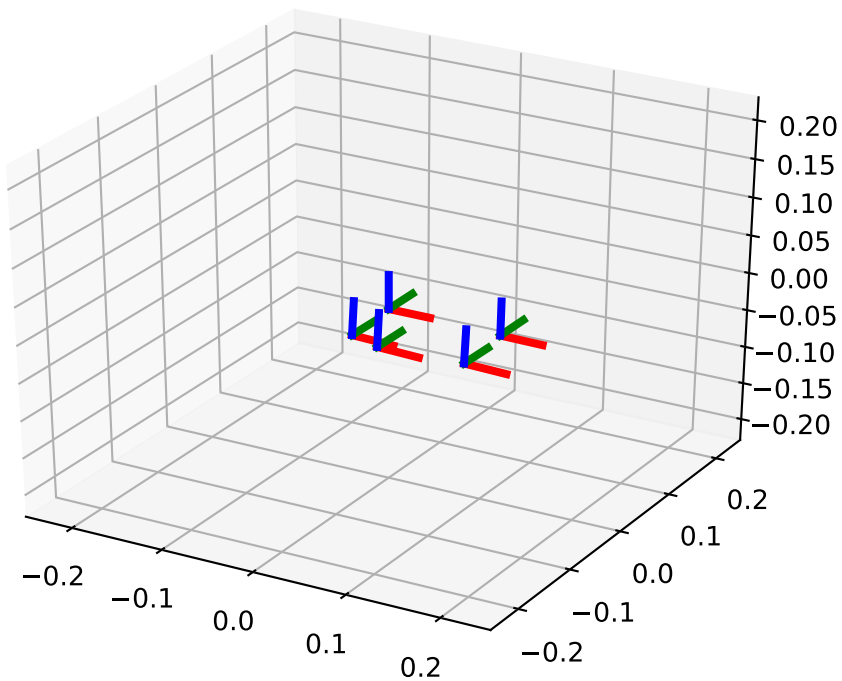
Size: 0.04 [m]

Spacing 0.01 [m]

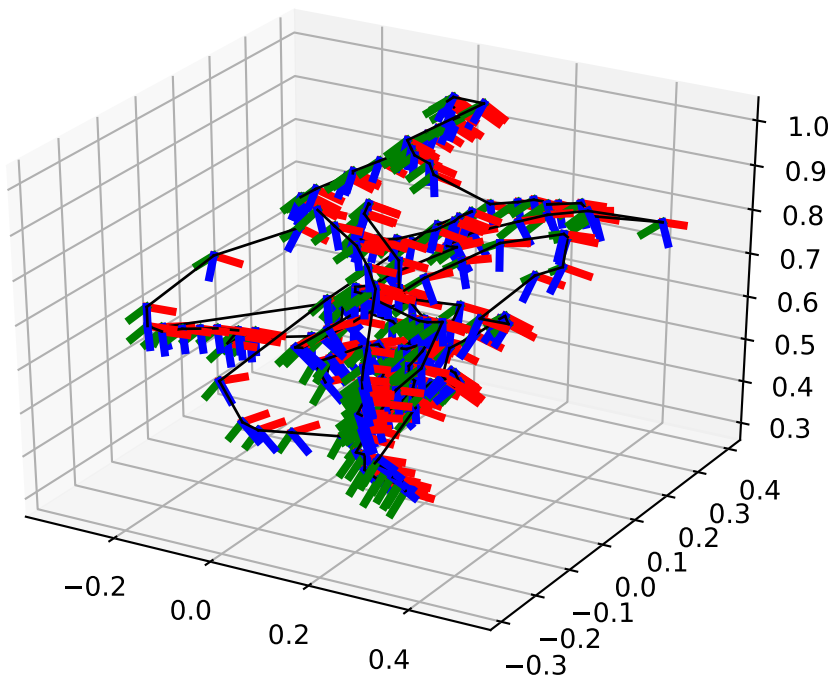
Inter-camera observations graph (edge weight=#mutual obs.)



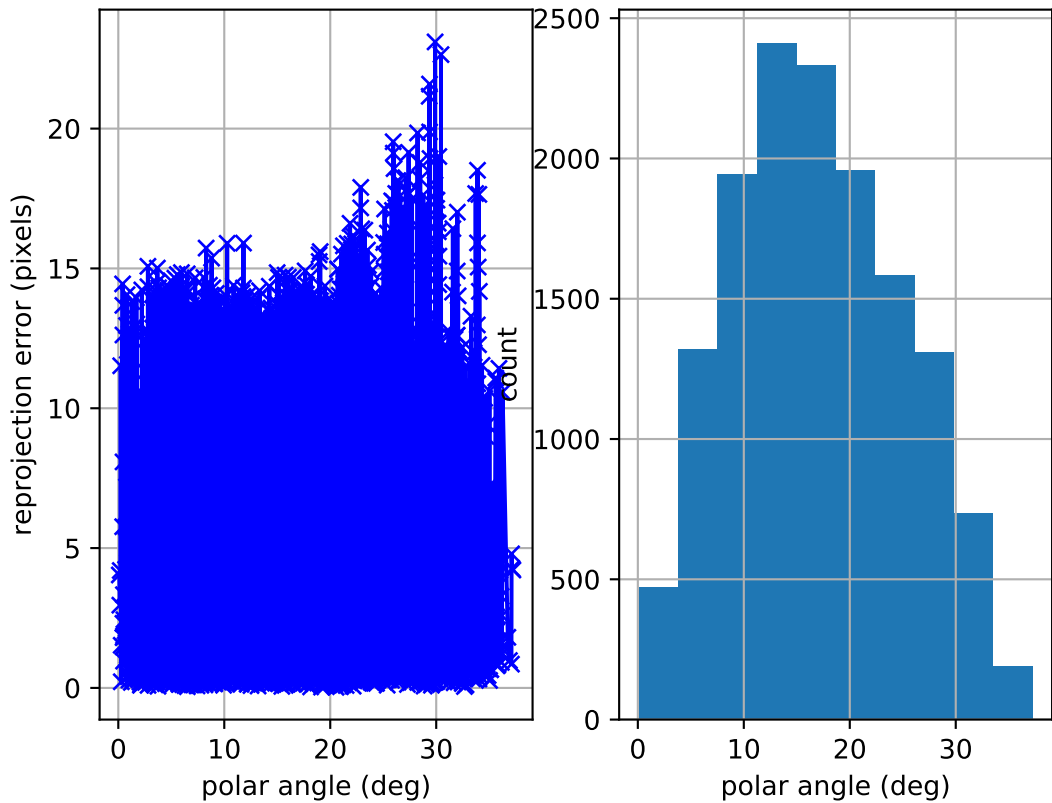
camera system



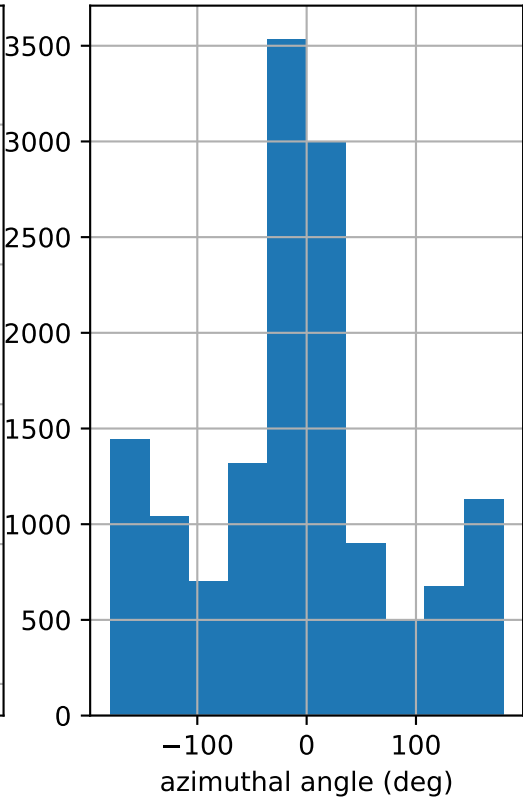
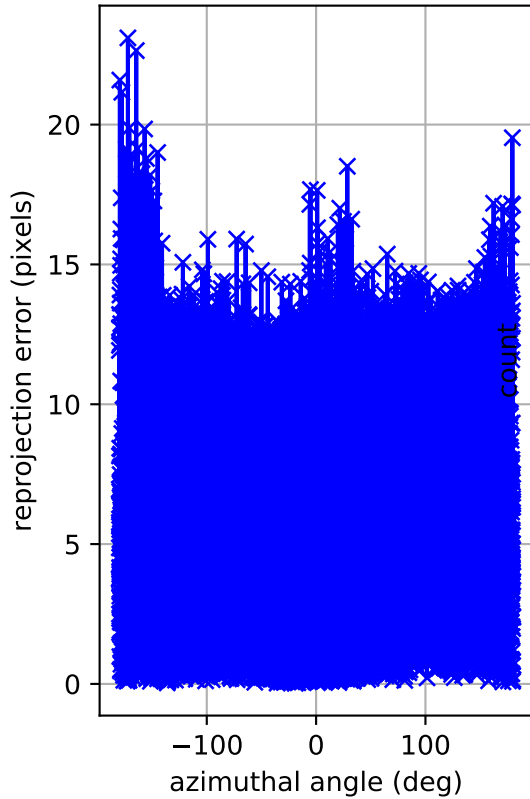
cam0: estimated poses



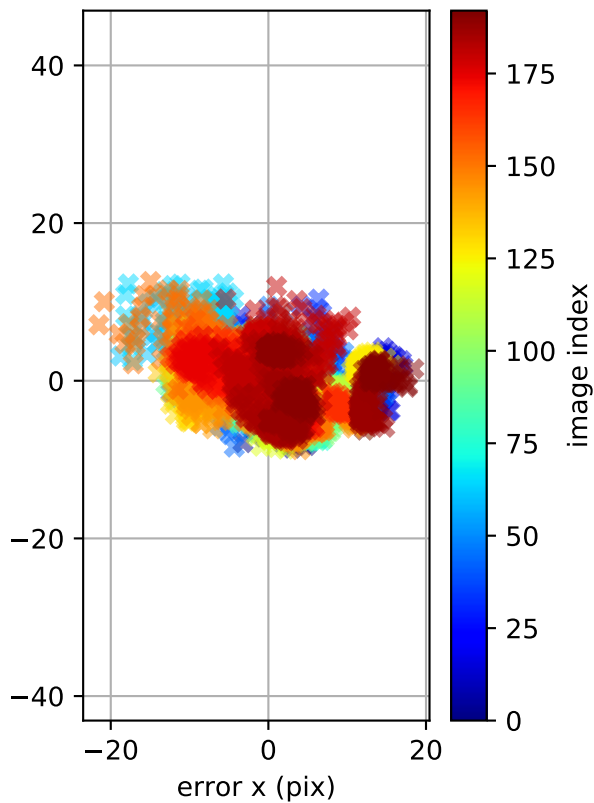
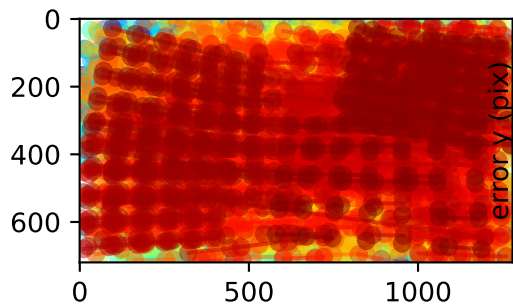
cam0: polar error



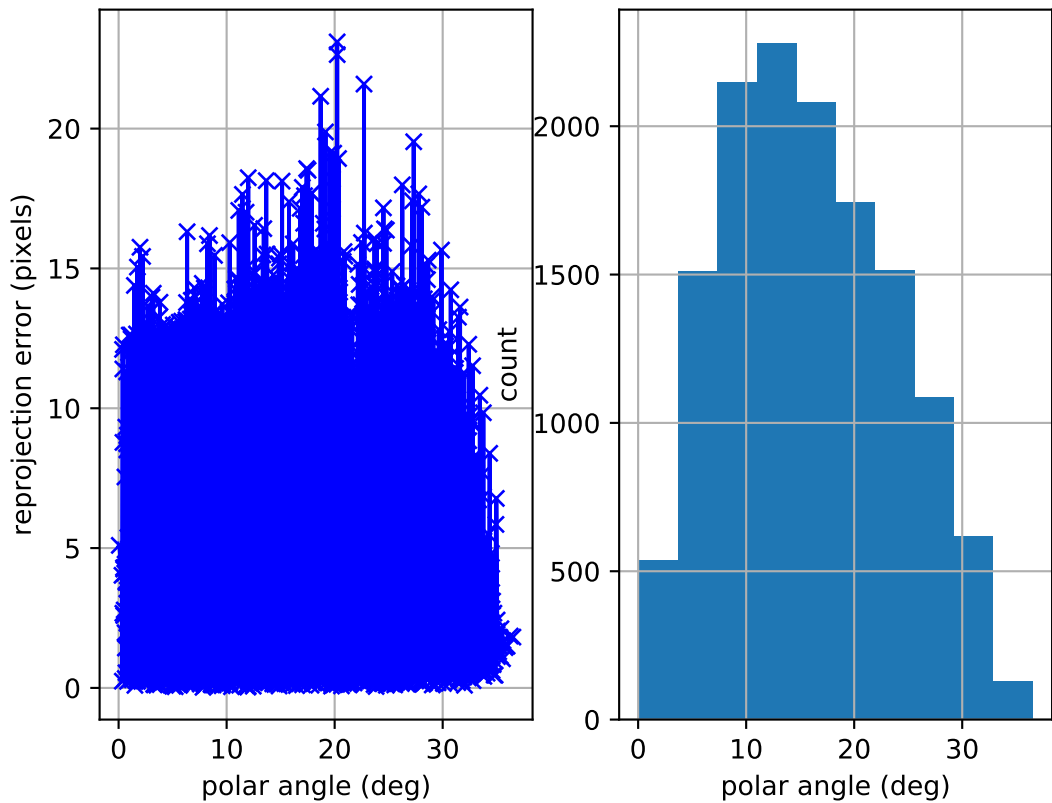
cam0: azimuthal error



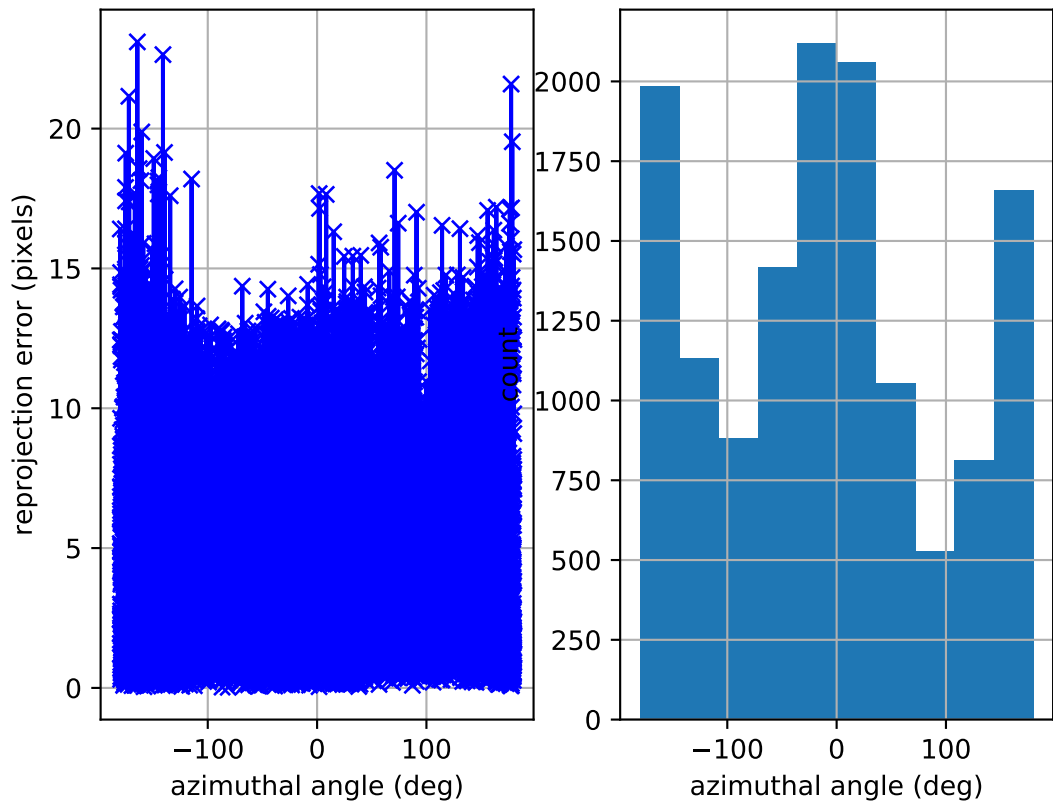
cam0: reprojection errors



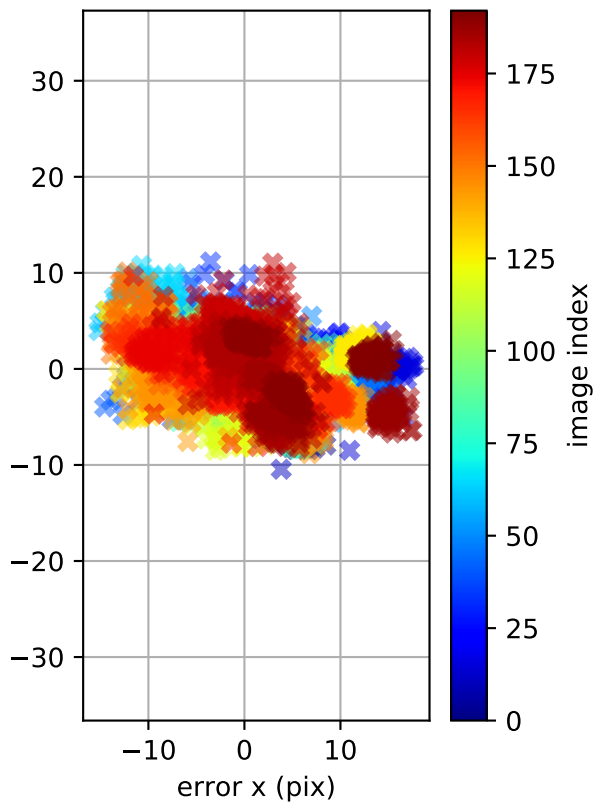
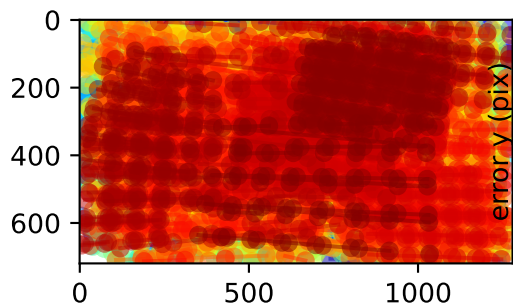
cam1: polar error



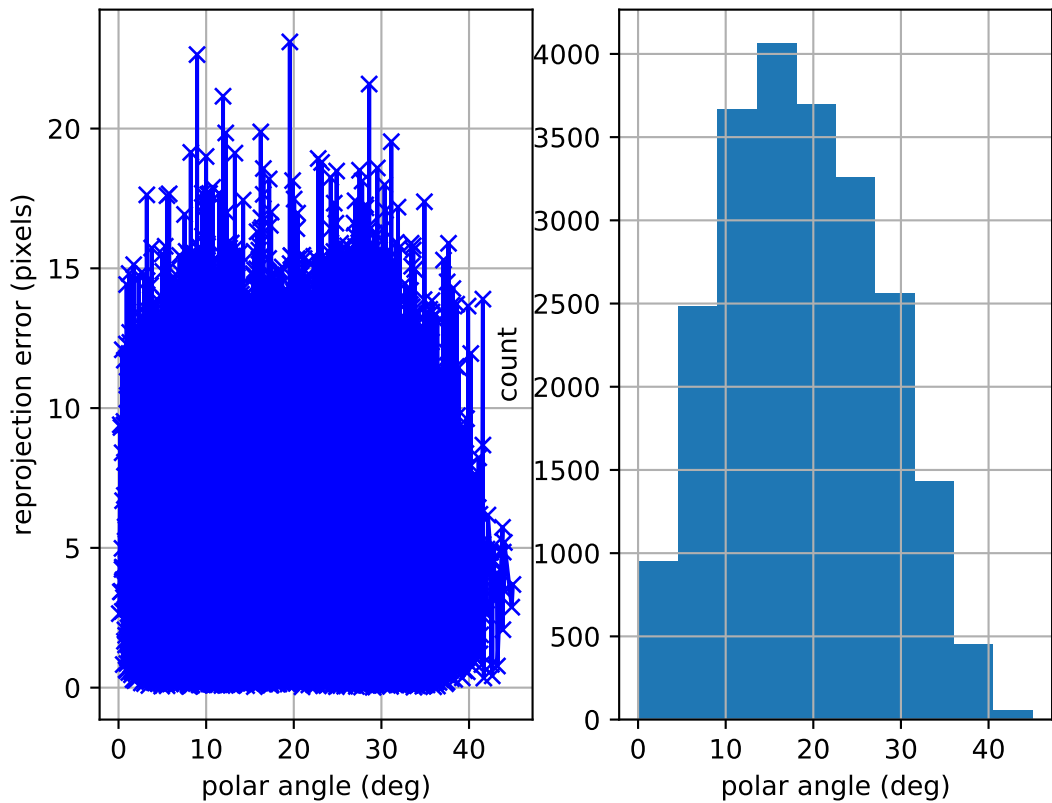
cam1: azimuthal error



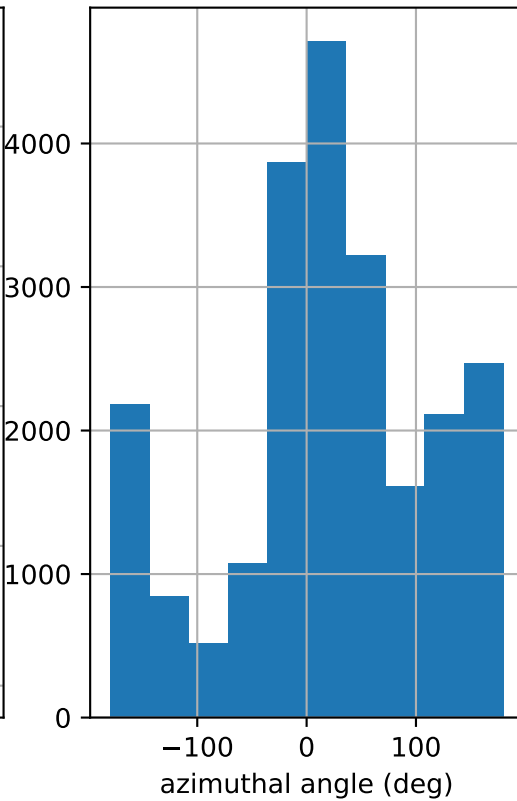
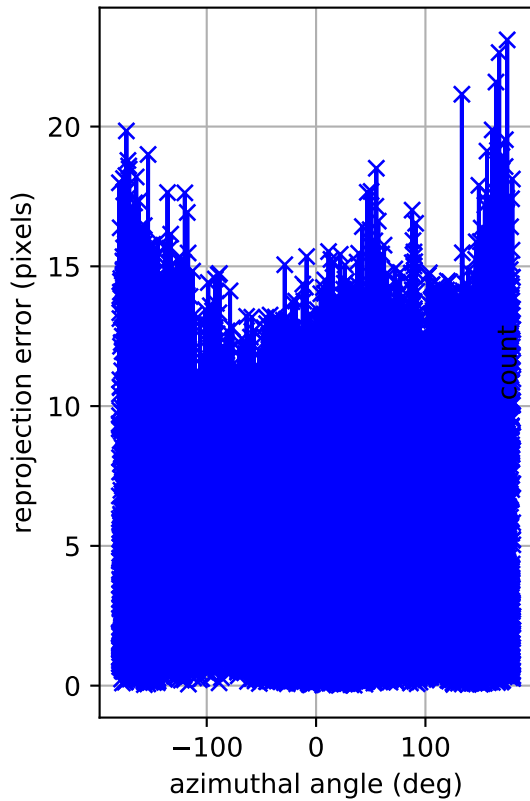
cam1: reprojection errors



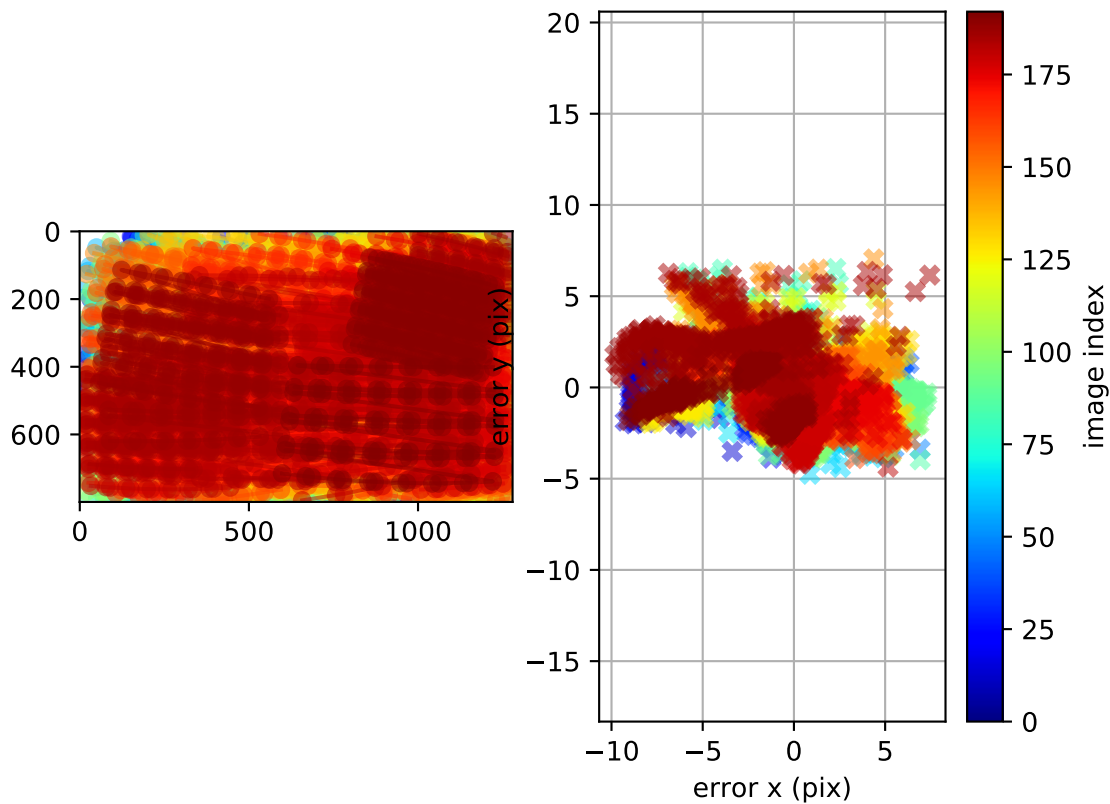
cam2: polar error



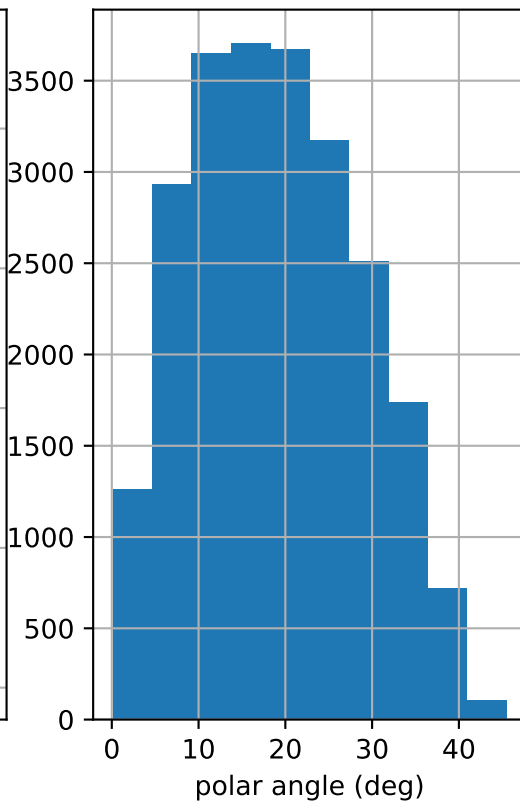
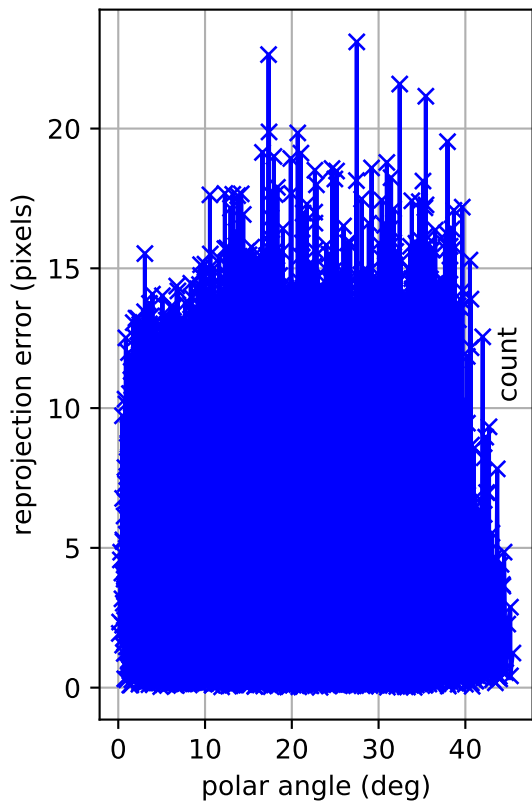
cam2: azimuthal error



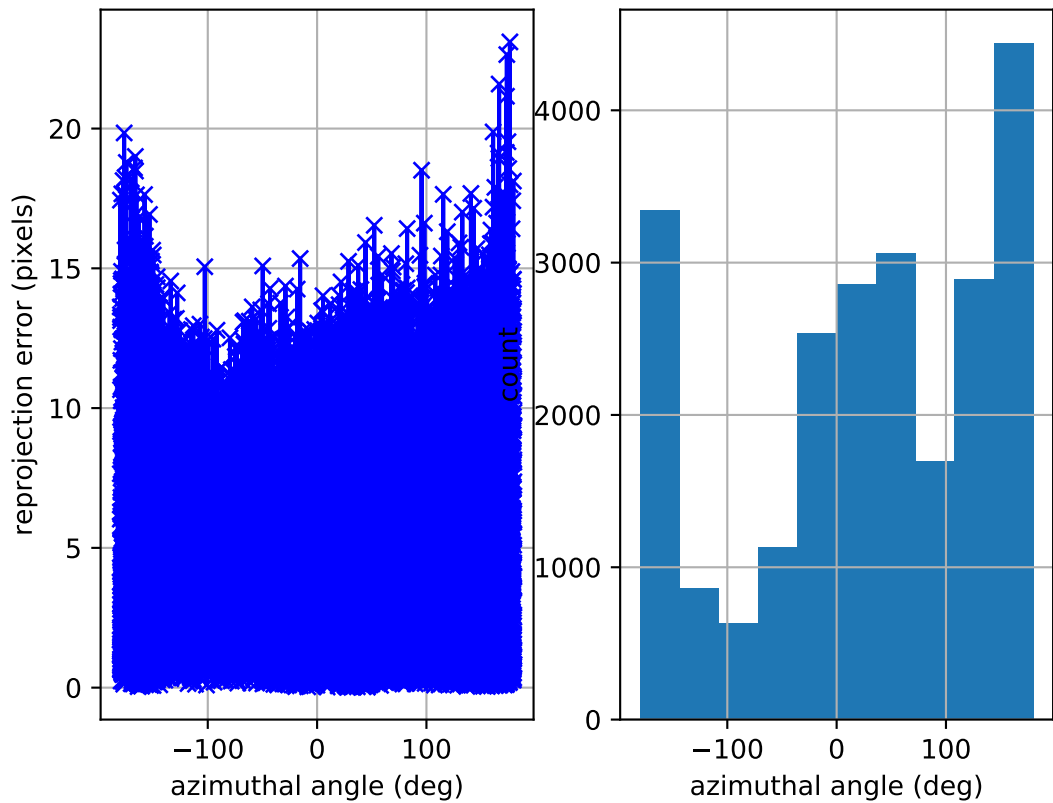
cam2: reprojection errors



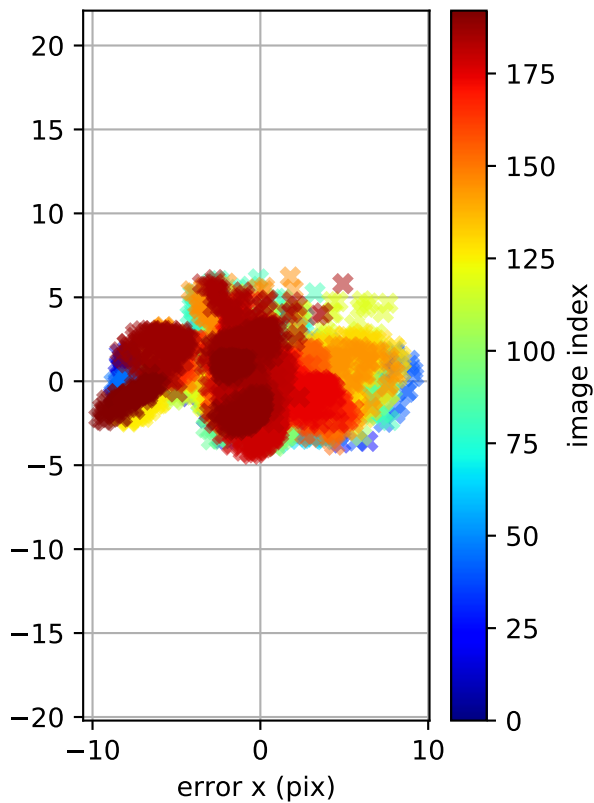
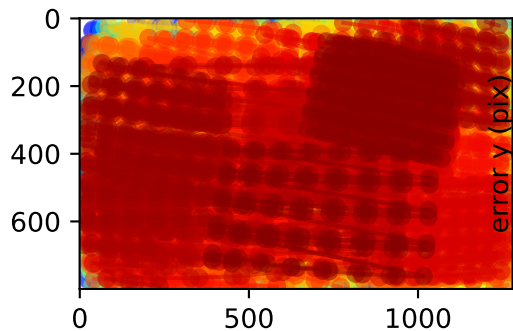
cam3: polar error



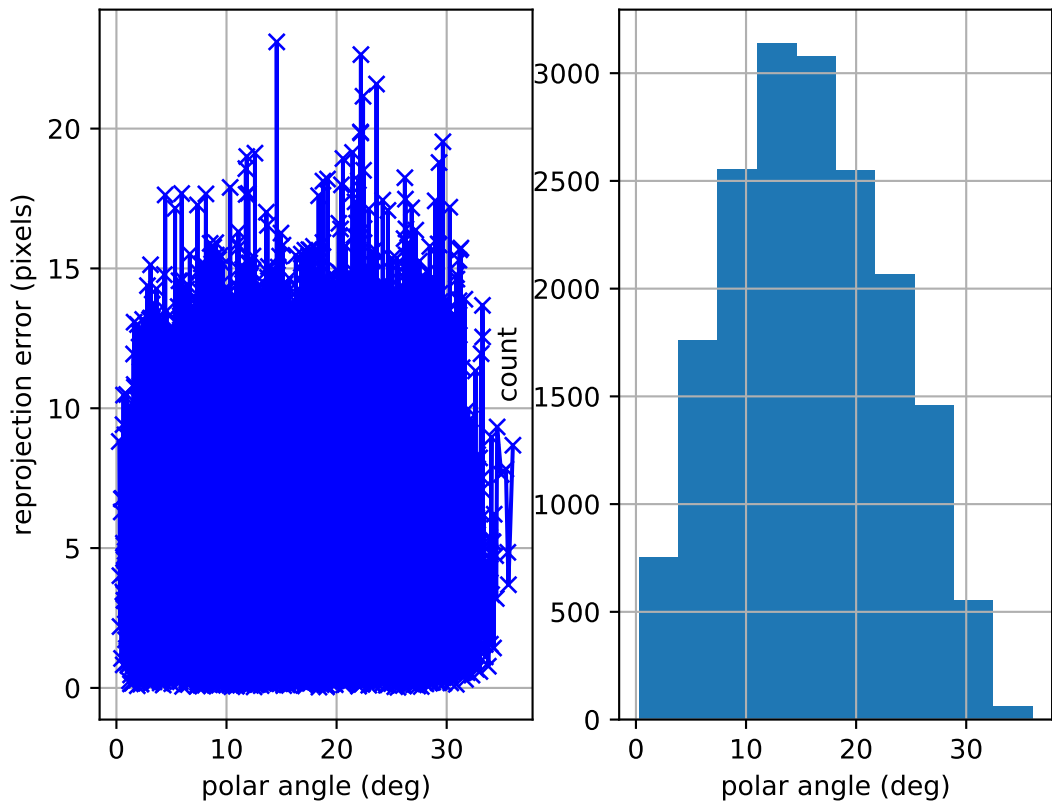
cam3: azimuthal error



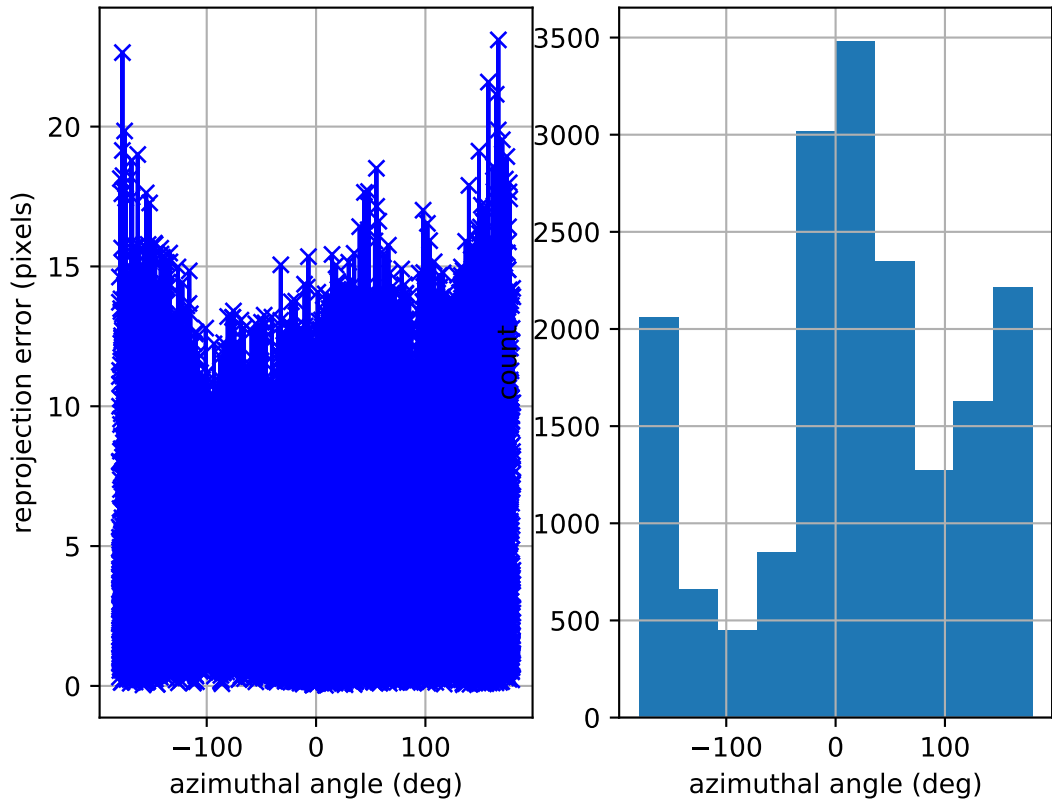
cam3: reprojection errors



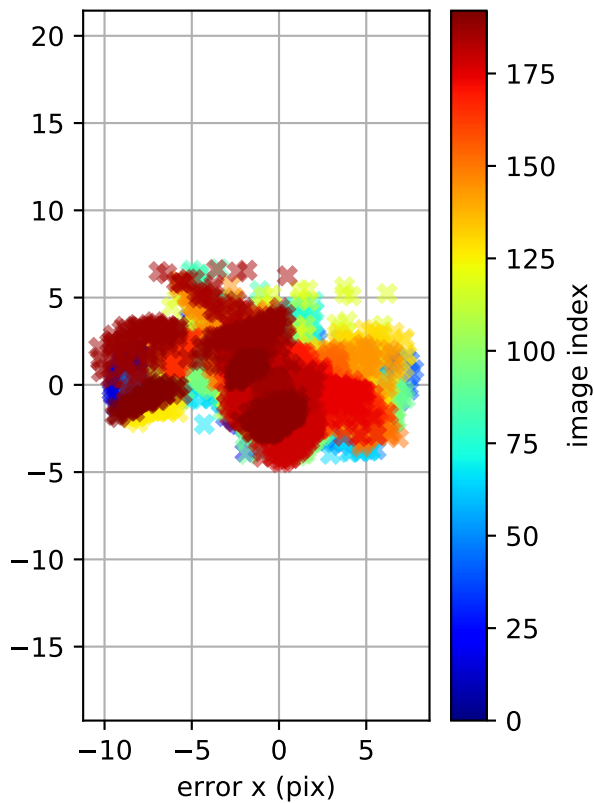
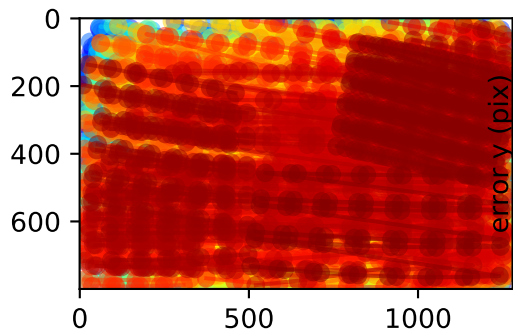
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

