

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04844637 0.08229217 -0.00014757 -0.00050909] +- [0.00095342 0.00204647 0.00007506 0.00005255]
projection: [1032.3395882 1031.83454564 637.28476752 363.56886839] +- [0.16421573 0.16018597 0.01599425
0.14578449]

reprojection error: [0.000062, -0.000008] +- [0.501088, 0.448331]

cam1 (/prophesee/right/events):

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

distortion: [-0.05787272 0.09066717 0.00102899 0.00070779] +- [0.00105677 0.00255532 0.00007537 0.00006525]
projection: [1031.66878651 1031.32710994 638.95903546 365.63673123] +- [0.05733734 0.05808698 0.00916644
0.04614271]

reprojection error: [0.000039, -0.000066] +- [0.593095, 0.532652]

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

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

distortion: [-0.3966956 0.16510538 0.00018344 0.00034423] +- [0.00056511 0.00102333 0.00005138 0.0000324]
projection: [1057.10141016 1057.22685756 677.16944783 334.57592259] +- [0.15083012 0.14828826 0.03121556
0.2055613]

reprojection error: [0.000073, -0.000110] +- [0.161623, 0.137282]

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

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

distortion: [-0.39524255 0.15806868 0.00000708 0.00081447] +- [0.00050963 0.00087518 0.00005472 0.00004337]
projection: [1052.75268468 1053.21453112 675.31621863 326.99690863] +- [0.15546591 0.15572172 0.03431771
0.22199359]

reprojection error: [0.000108, -0.000150] +- [0.168200, 0.135982]

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

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

distortion: [-0.41561262 0.18809682 0.00007138 -0.0000194] +- [0.00073345 0.00175636 0.00005247 0.0000385]
projection: [1263.10114714 1263.15821326 651.9750113 367.11415999] +- [0.1436026 0.14048779 0.01157265
0.06924146]

reprojection error: [0.000128, -0.000066] +- [0.236337, 0.219348]

baseline T_1_0:

q: [-0.00134695 0.00209107 -0.00024193 0.99999688] +- [0.00011145 0.00005861 0.00004086]

t: [-0.12031286 0.00098702 -0.00052926] +- [0.00003801 0.00003313 0.00010688]

baseline T_2_1:

q: [-0.00042253 -0.00258041 -0.00517888 0.99998317] +- [0.00021287 0.00006246 0.00003848]

t: [0.1200408 0.06910896 0.00392141] +- [0.00003523 0.00003322 0.00010801]

baseline T_3_2:

q: [0.00031998 -0.00260504 0.00024963 0.99999652] +- [0.00030448 0.00006479 0.00003316]

t: [-0.11993811 -0.00007311 0.00127721] +- [0.00003309 0.00003038 0.00013053]

baseline T_4_3:

q: [0.00124999 0.00354259 0.0004273 0.99999285] +- [0.00024802 0.00005588 0.00003191]

t: [0.08874837 0.0062362 0.00271728] +- [0.00002969 0.00002896 0.00012659]

Target configuration

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Type: aprilgrid

Tags:

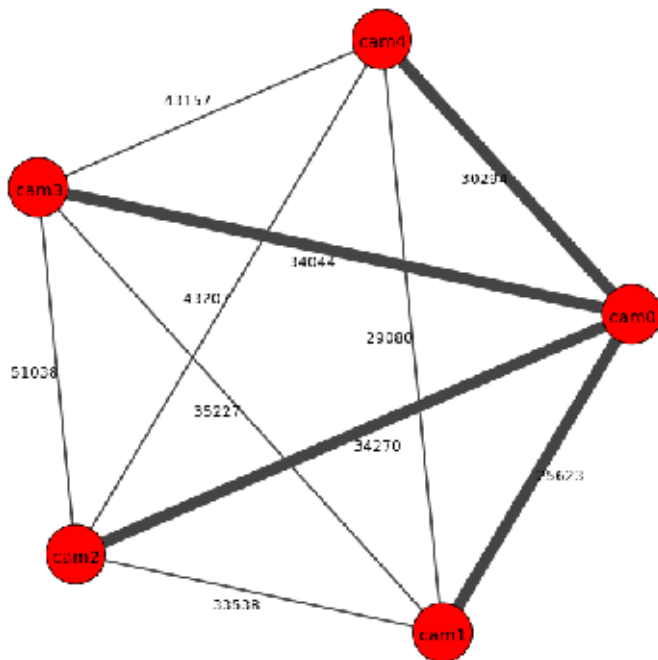
Rows: 5

Cols: 7

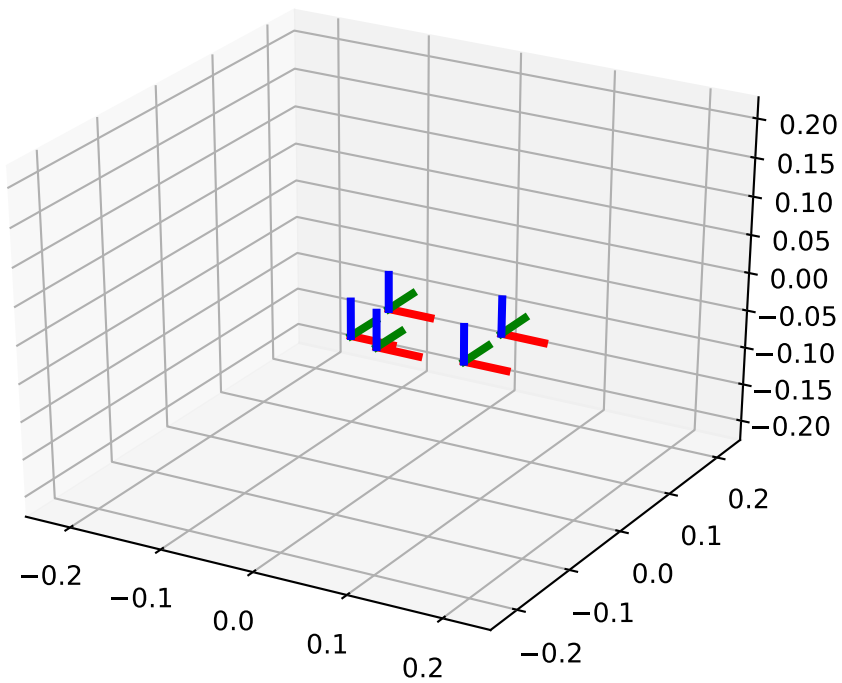
Size: 0.04 [m]

Spacing 0.01 [m]

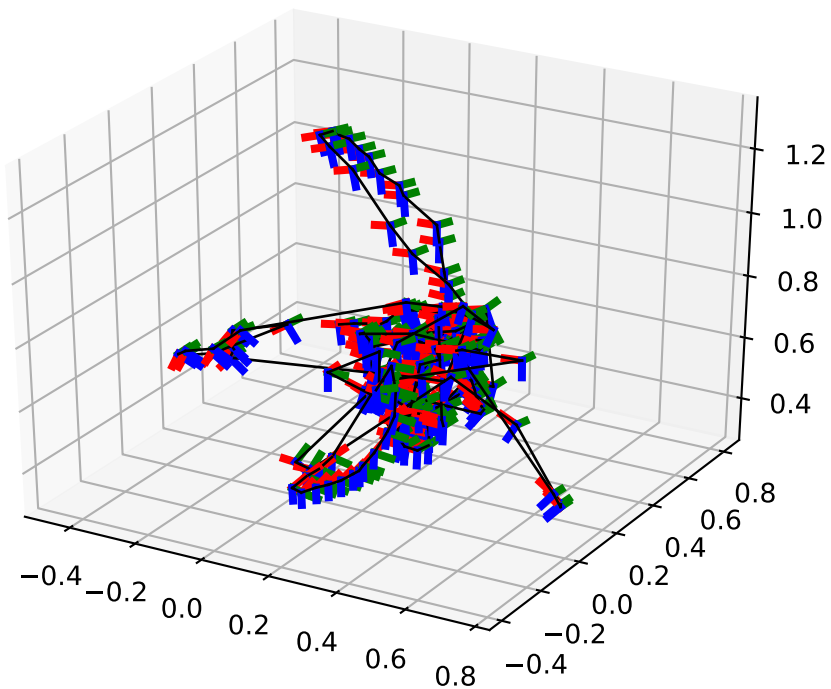
Inter-camera observations graph (edge weight=#mutual obs.)



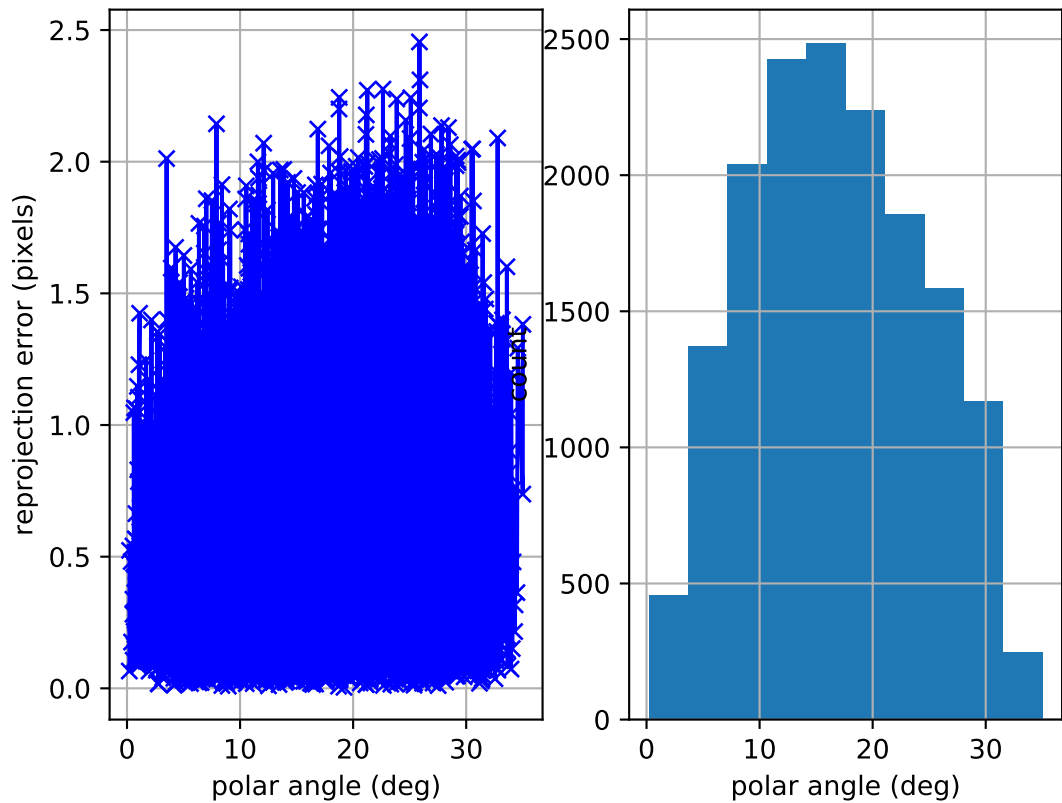
camera system



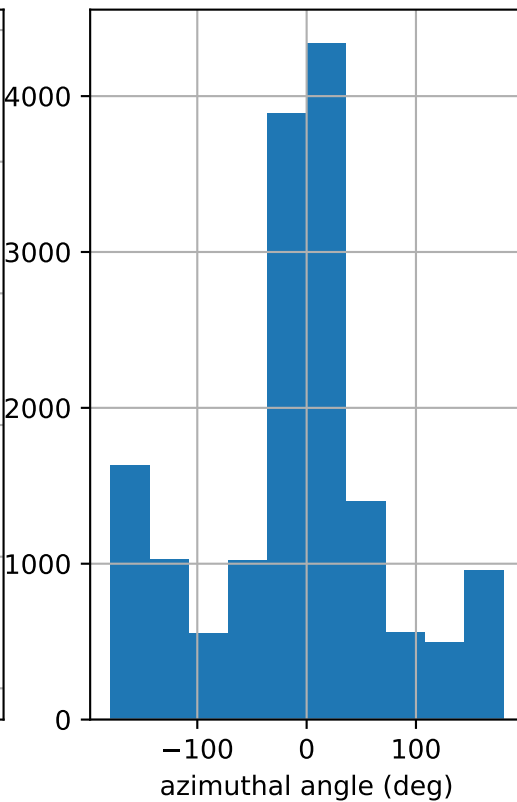
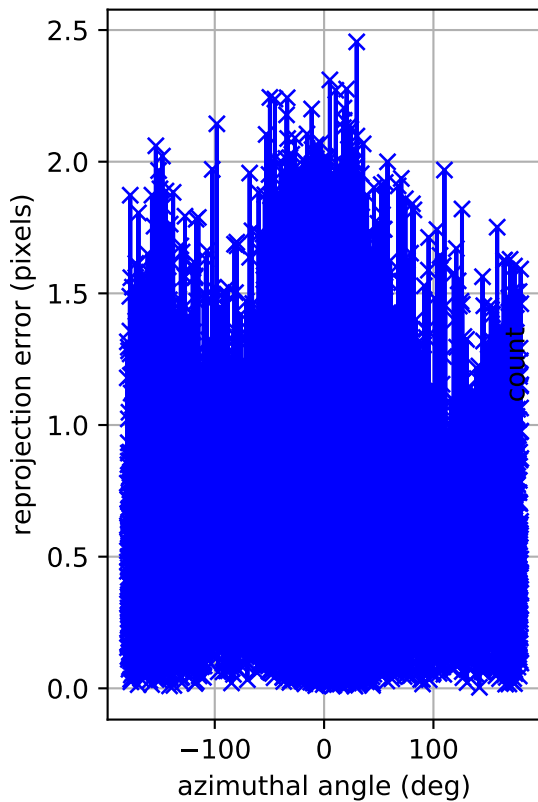
cam0: estimated poses



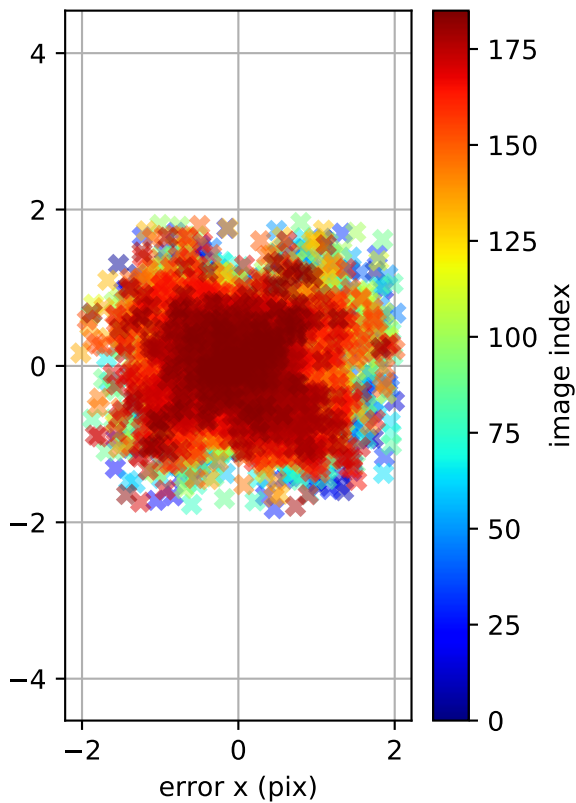
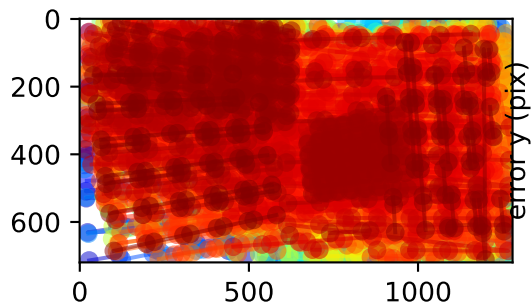
cam0: polar error



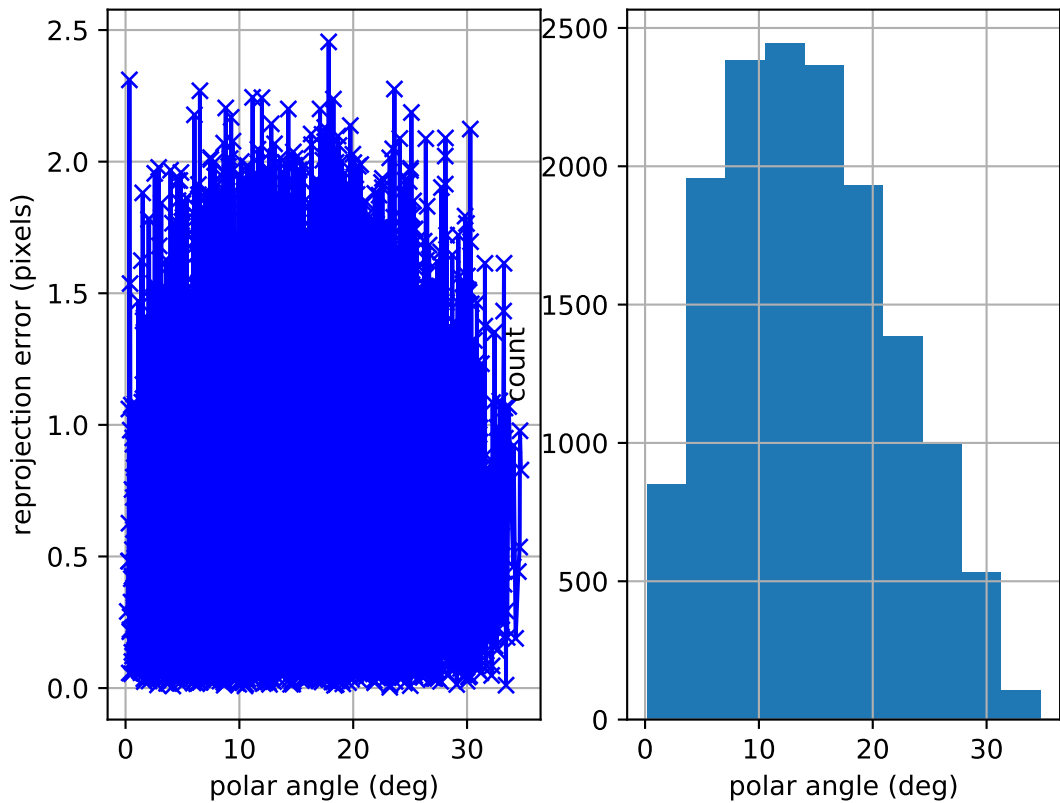
cam0: azimuthal error



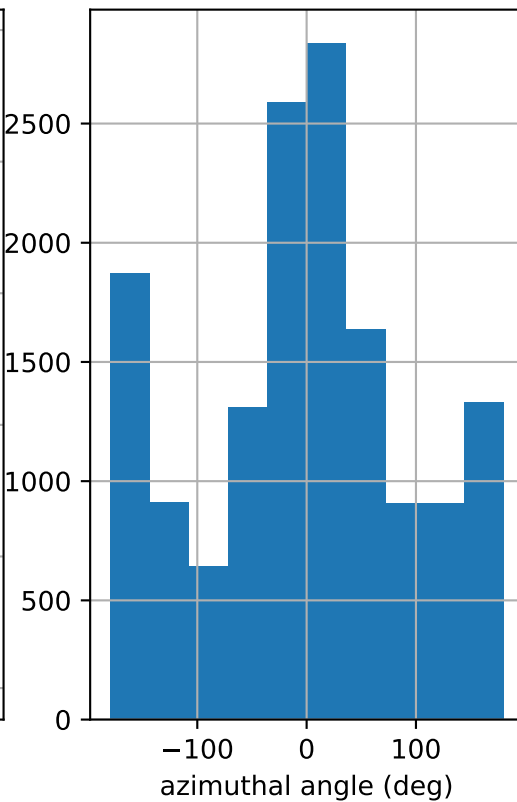
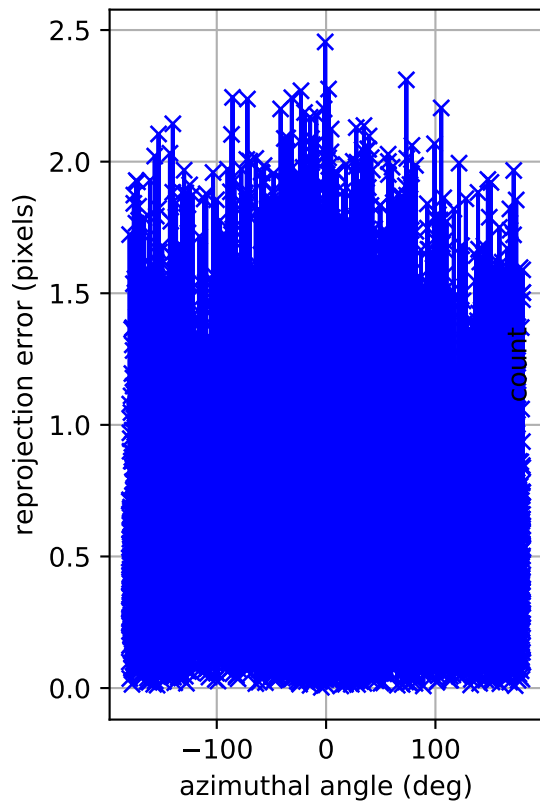
cam0: reprojection errors



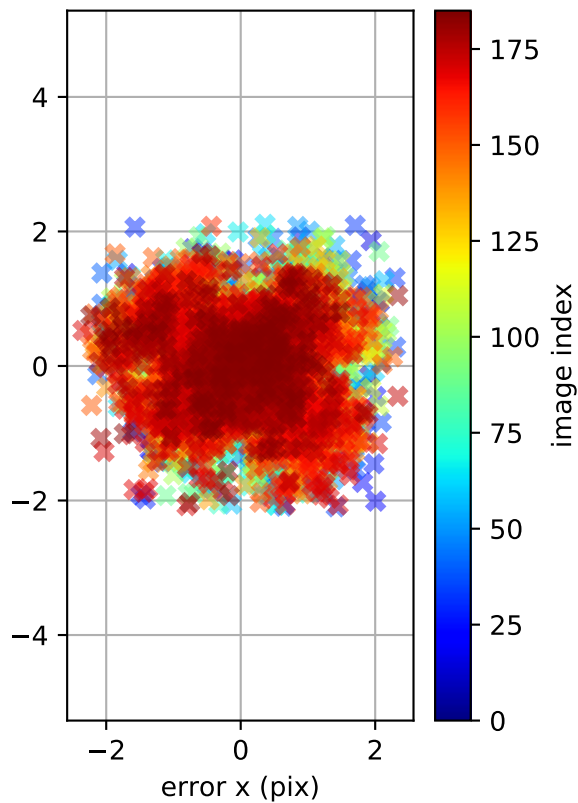
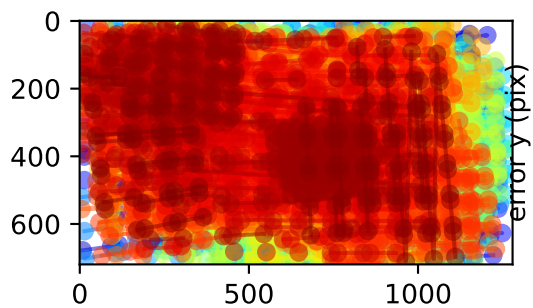
cam1: polar error



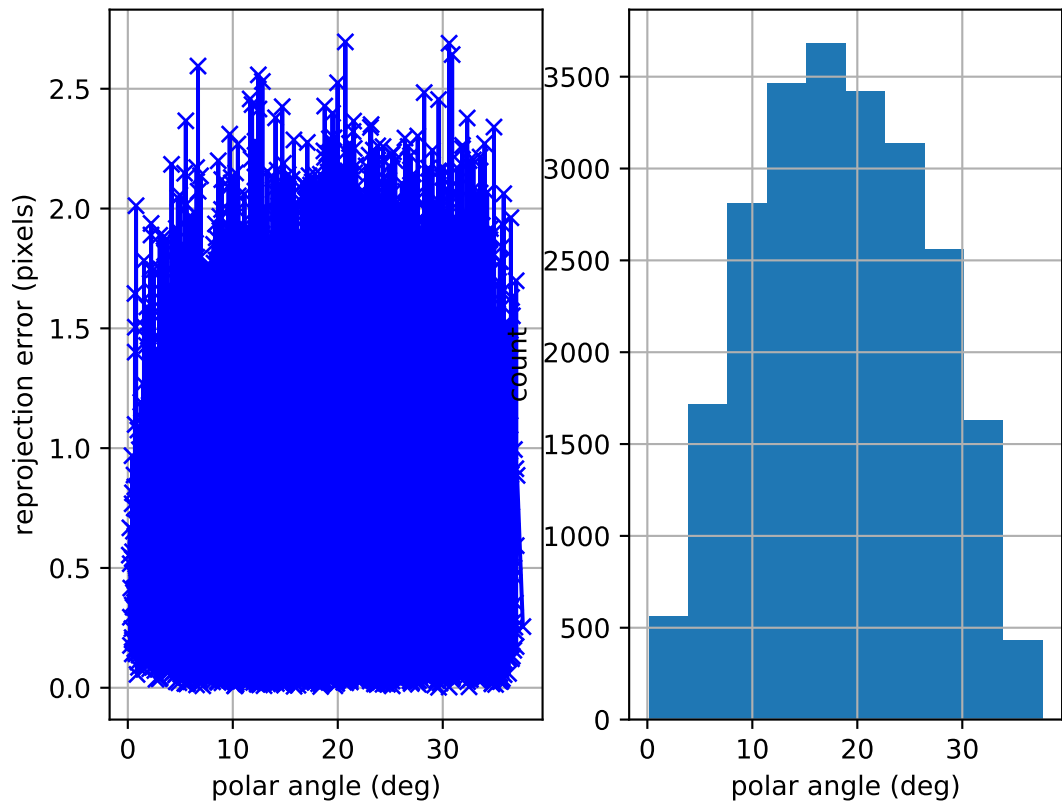
cam1: azimuthal error



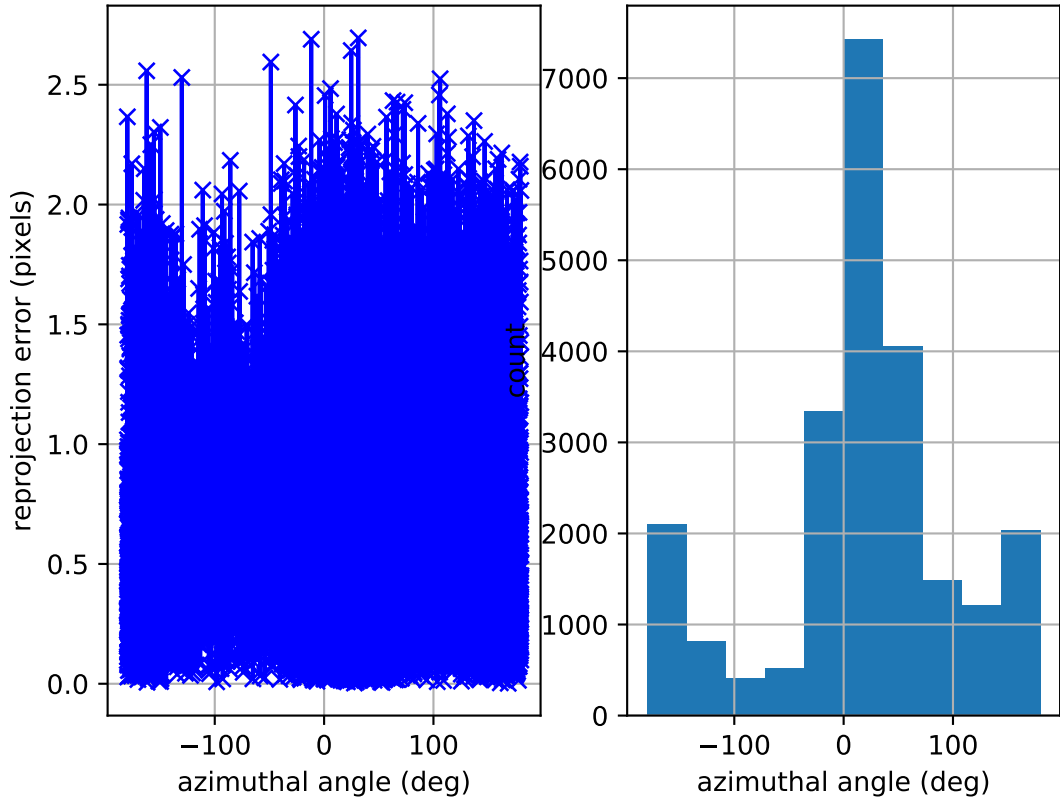
cam1: reprojection errors



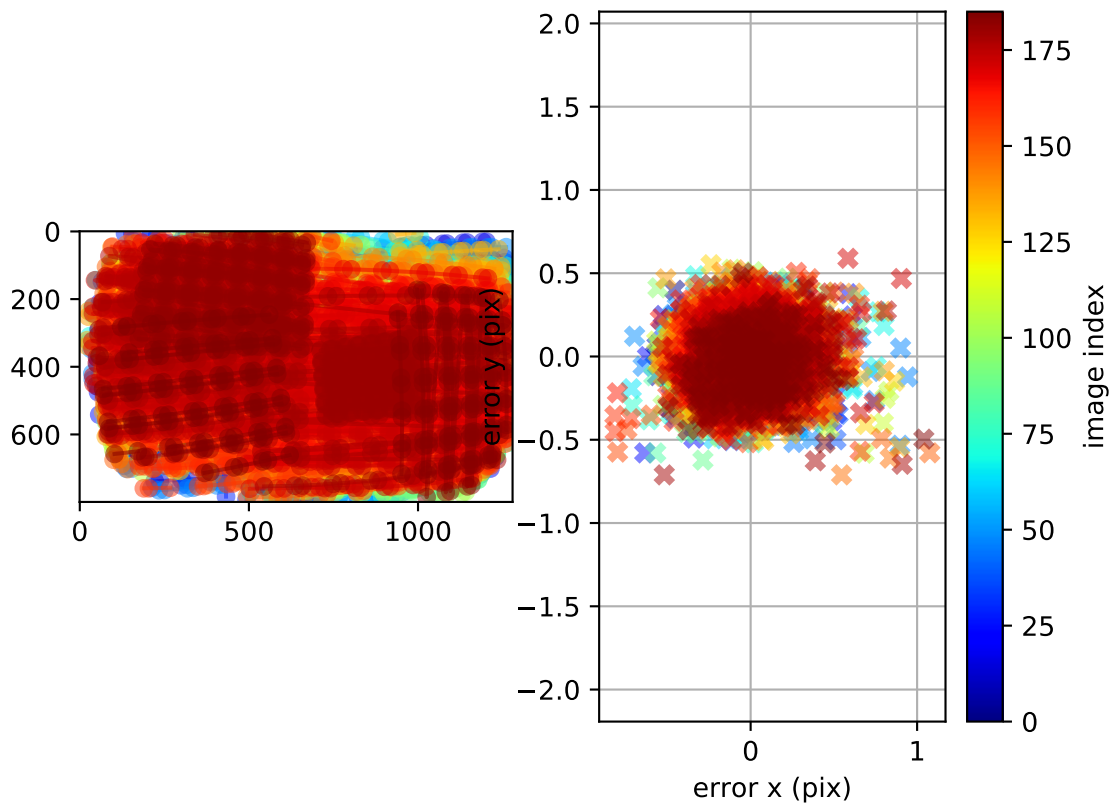
cam2: polar error



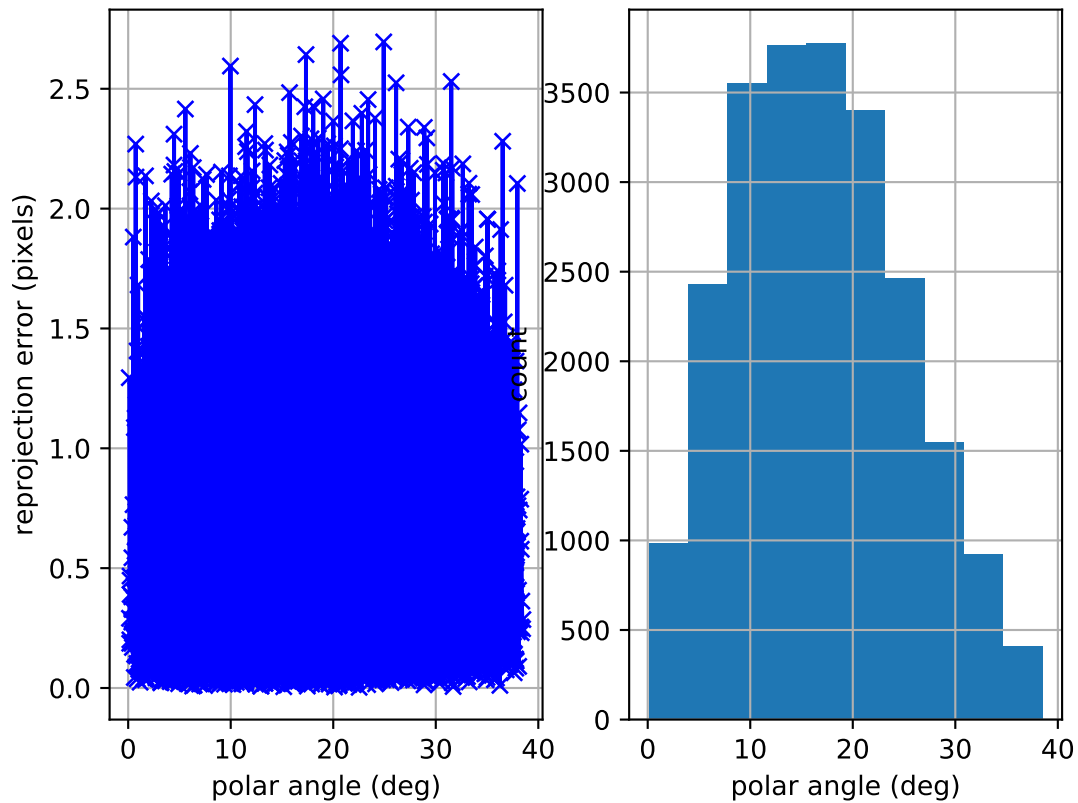
cam2: azimuthal error



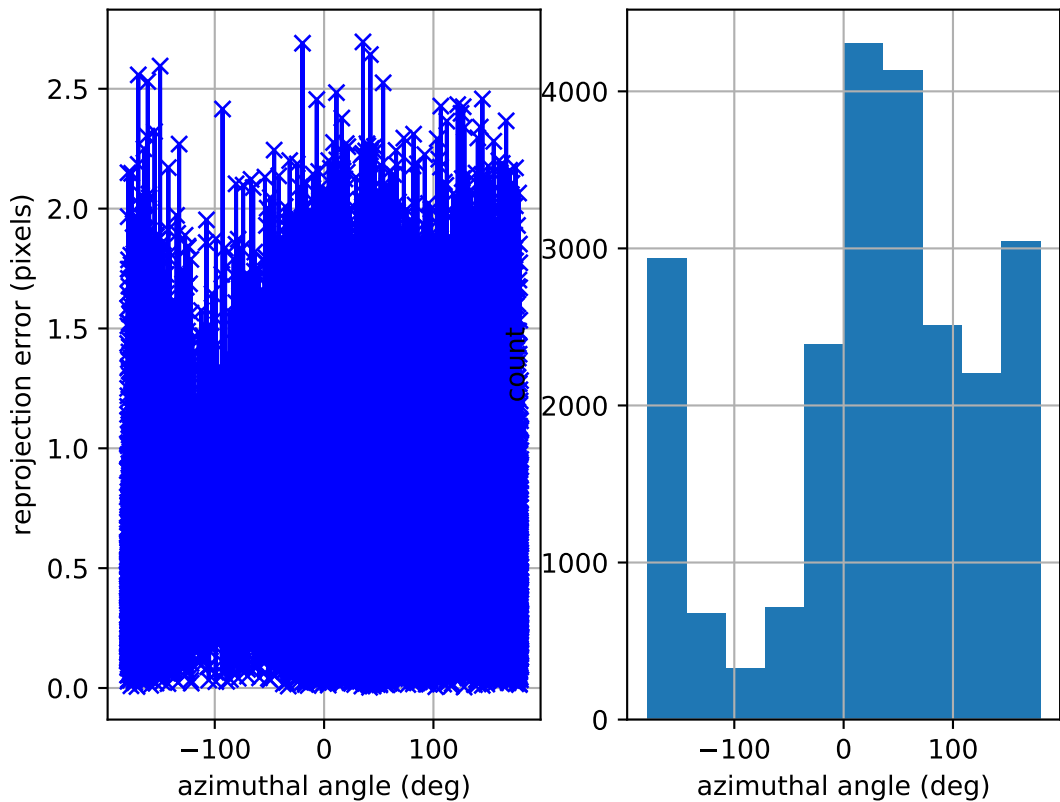
cam2: reprojection errors



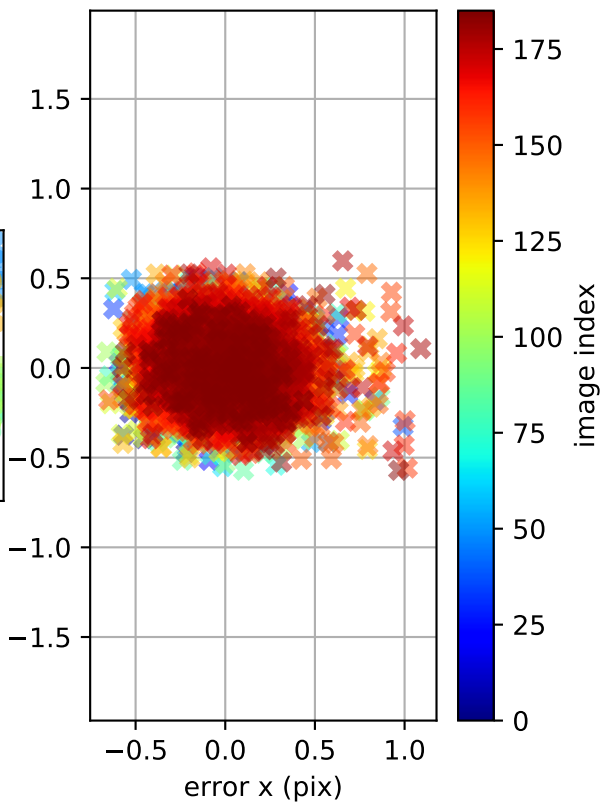
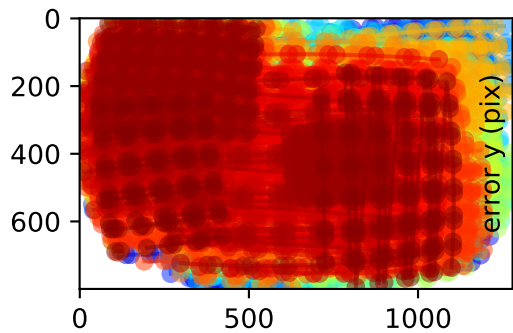
cam3: polar error



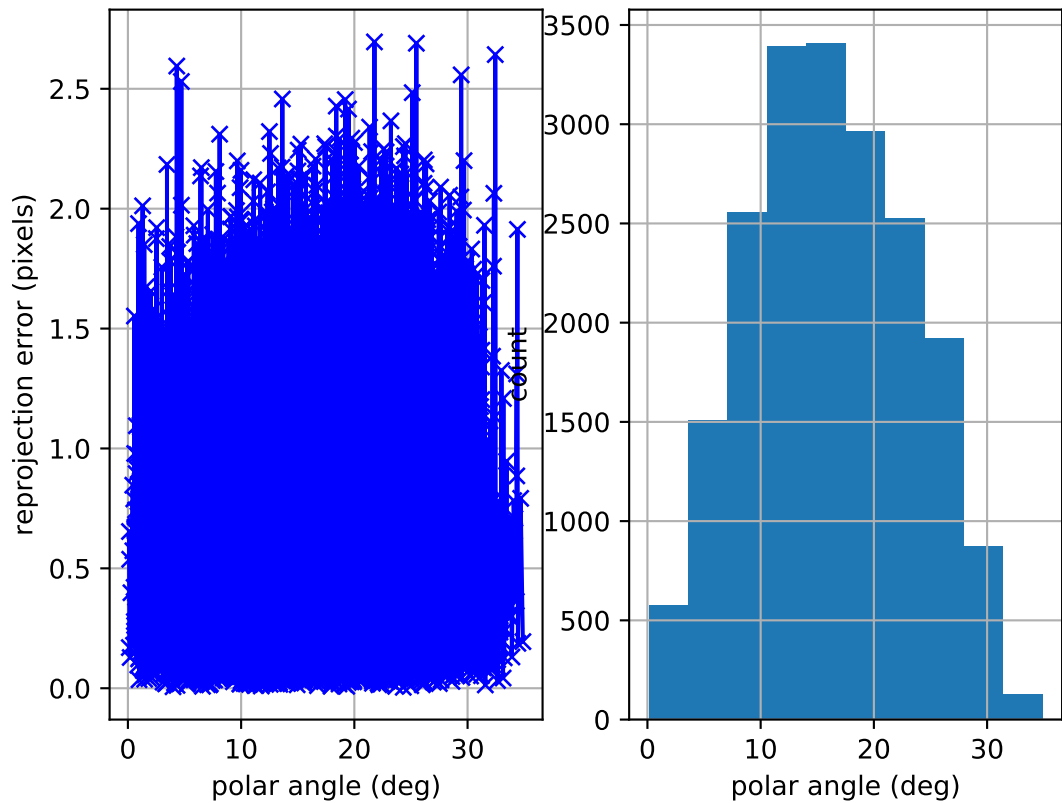
cam3: azimuthal error



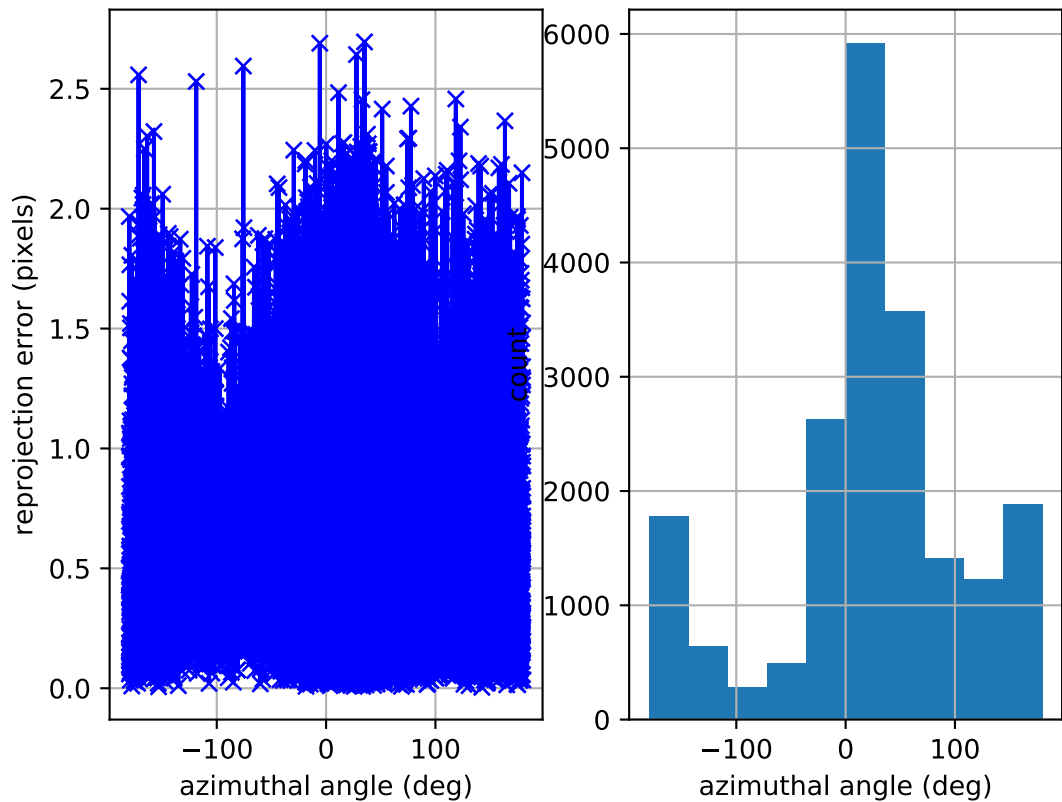
cam3: reprojection errors



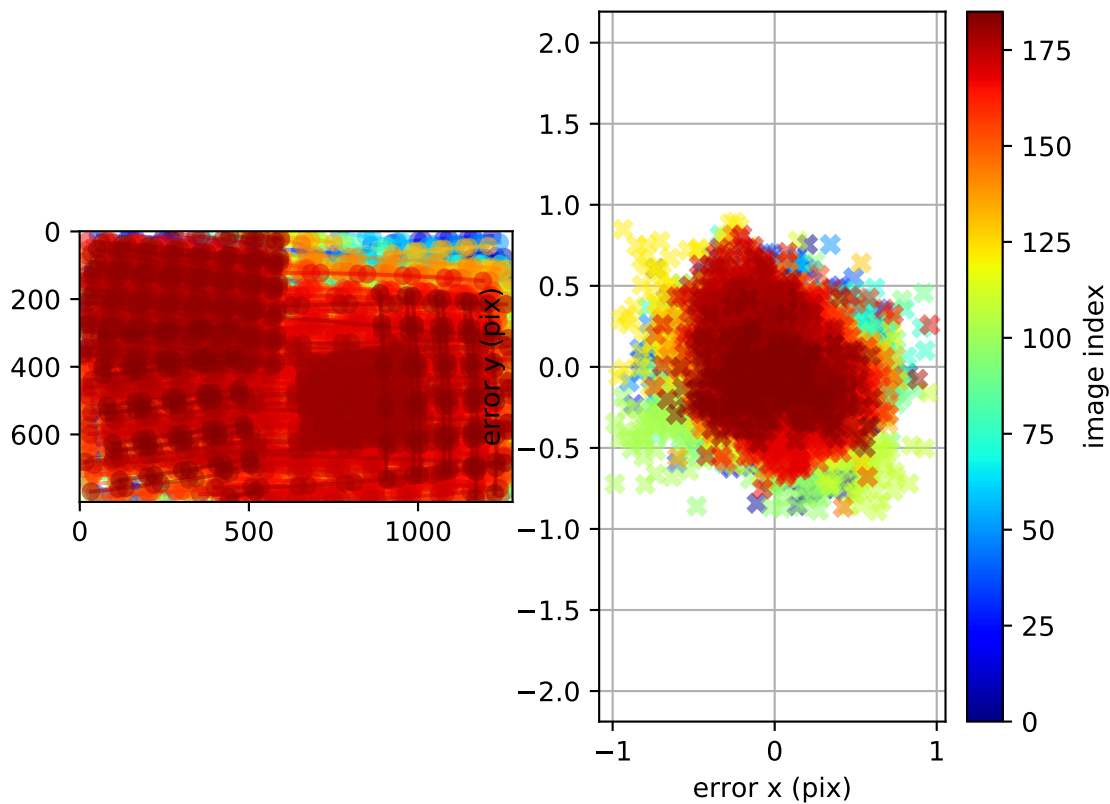
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

