

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.0431334 0.07288198 0.00058351 -0.00127561] +- [0.00107028 0.00214978 0.00010093 0.00006768]
projection: [1031.84262859 1030.10381777 635.71409589 365.59991372] +- [0.15210615 0.14650963 0.02453825 0.22400533]

reprojection error: [-0.000425, 0.000064] +- [0.729431, 0.672676]

cam1 (/prophesee/right/events):

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

distortion: [-0.0456886 0.07024343 0.001102 -0.00068348] +- [0.00109736 0.00233757 0.00010168 0.00006521]
projection: [1030.46186128 1029.51180204 635.69022466 364.32444857] +- [0.15107201 0.14412885 0.03697797 0.24398608]

reprojection error: [-0.000227, 0.000070] +- [0.795601, 0.658610]

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

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

distortion: [-0.38857313 0.15038306 -0.00056101 0.00047074] +- [0.0005256 0.00082237 0.00005425 0.00004233]
projection: [1056.37914187 1056.34177867 674.47094517 337.53990227] +- [0.12458322 0.12313598 0.21626764 0.20075546]

reprojection error: [0.000171, -0.000080] +- [0.504327, 0.441607]

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

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

distortion: [-0.39138058 0.15039493 -0.0006628 0.00117956] +- [0.00046305 0.00069097 0.00005797 0.0000424]
projection: [1052.65545508 1052.79551471 671.63303136 330.54651619] +- [0.12305848 0.12107373 0.26880511 0.19330217]

reprojection error: [0.000591, -0.000034] +- [0.497549, 0.423116]

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

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

distortion: [-0.41631266 0.1934814 -0.00053057 -0.00015221] +- [0.01046439 0.03107987 0.00077558 0.00061091]
projection: [1269.18576893 1269.52626354 654.87661083 366.12841687] +- [0.00096871 0.00082022 0.0000617 0.00017206]

reprojection error: [0.000229, 0.000069] +- [0.347129, 0.363075]

baseline T_1_0:

q: [0.00023416 0.00137866 -0.0003044 0.99999898] +- [0.00038384 0.00007739 0.00004406]

t: [-0.1201884 0.00106054 0.00010729] +- [0.00003623 0.0000299 0.00011624]

baseline T_2_1:

q: [-0.00249056 -0.00241466 -0.00584467 0.9999769] +- [0.00036633 0.00017699 0.00004283]

t: [0.12028657 0.0691409 0.00395558] +- [0.00003181 0.00002842 0.0001082]

baseline T_3_2:

q: [-0.0000026 -0.00243479 0.00023744 0.99999701] +- [0.00029452 0.00046369 0.00003605]

t: [-0.11998998 -0.00004934 0.00143349] +- [0.00002869 0.00002477 0.00009726]

baseline T_4_3:

q: [0.00279313 0.00608988 0.00030593 0.99997751] +- [0.00081409 0.00085303 0.00025109]

t: [0.08889541 0.00662579 0.00475153] +- [0.00030595 0.00029593 0.00025355]

Target configuration

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Type: aprilgrid

Tags:

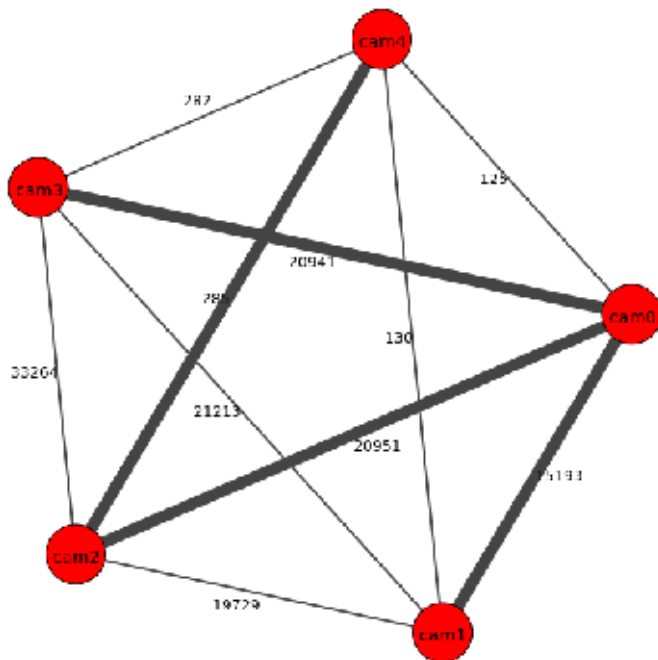
Rows: 5

Cols: 7

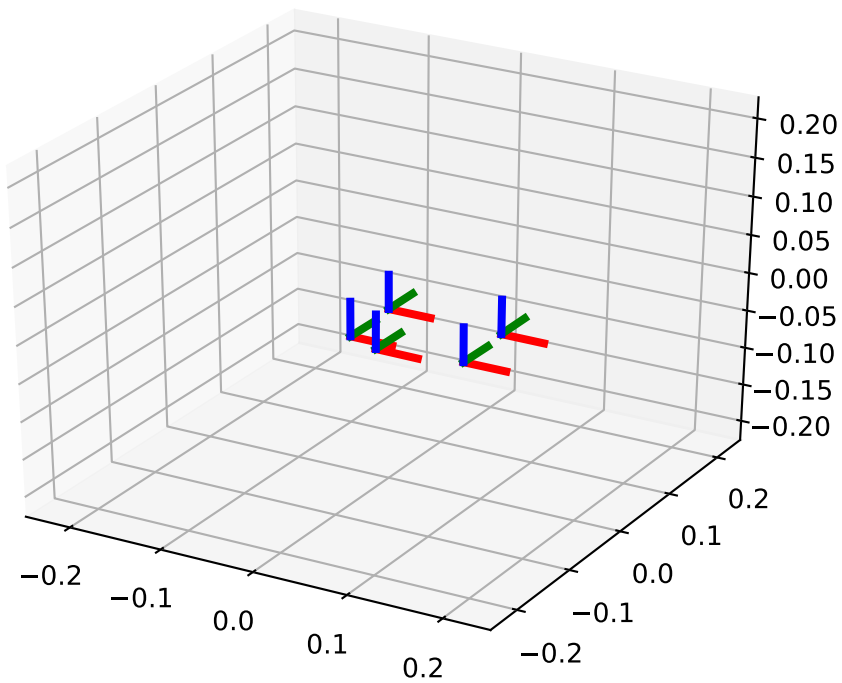
Size: 0.04 [m]

Spacing 0.01 [m]

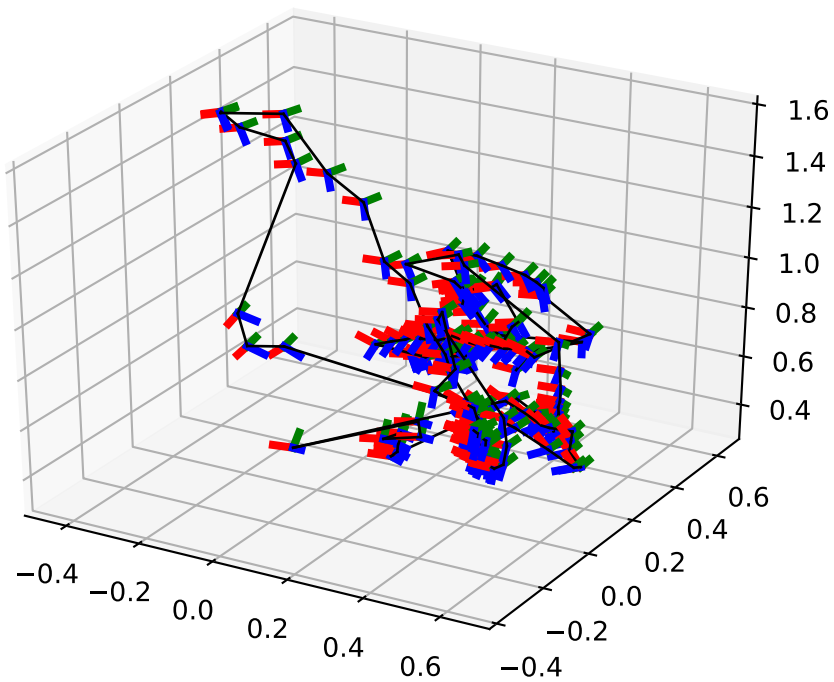
Inter-camera observations graph (edge weight=#mutual obs.)



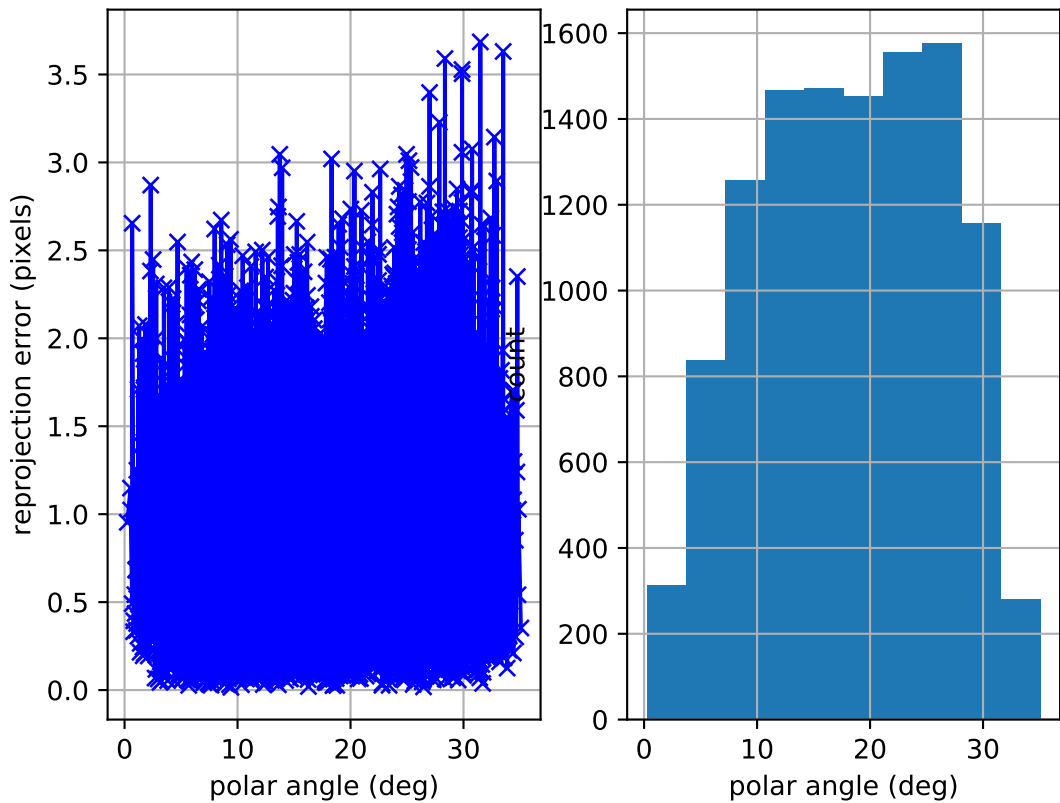
camera system



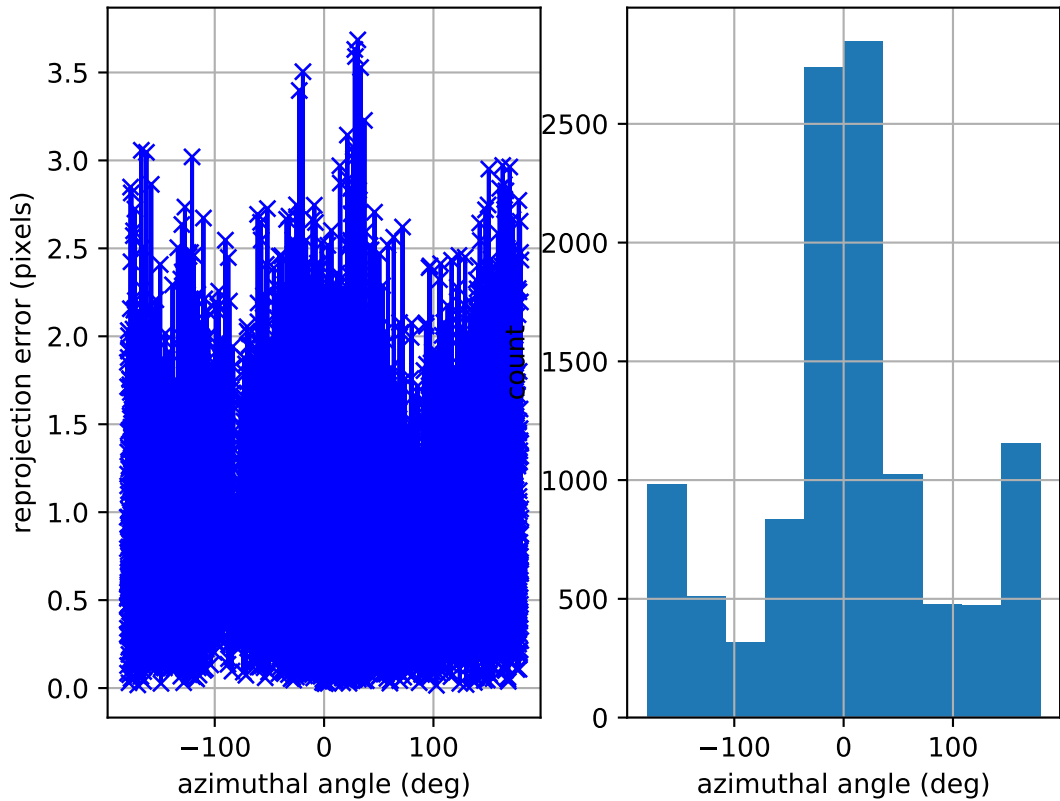
cam0: estimated poses



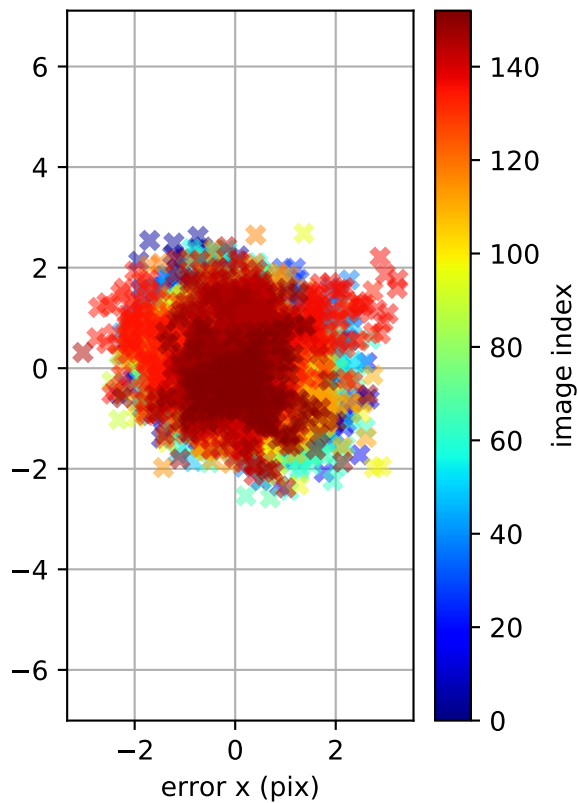
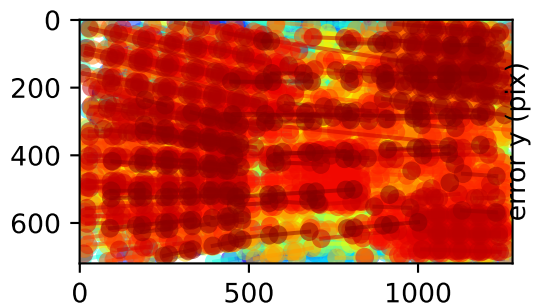
cam0: polar error



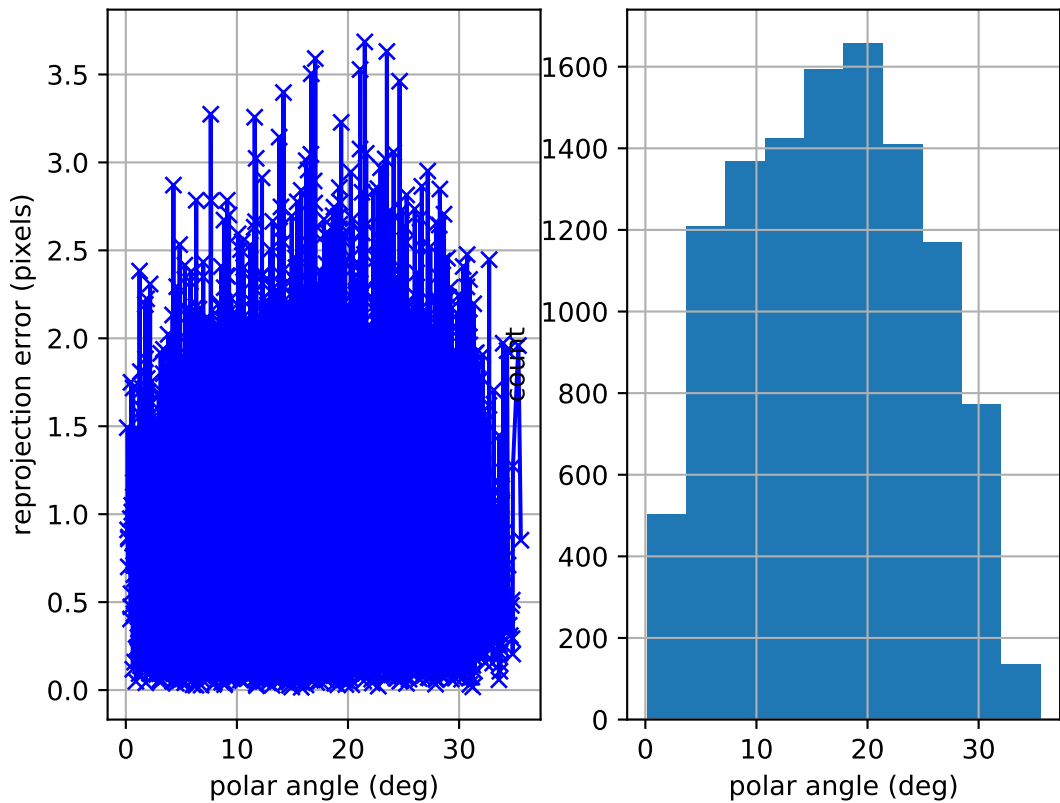
cam0: azimuthal error



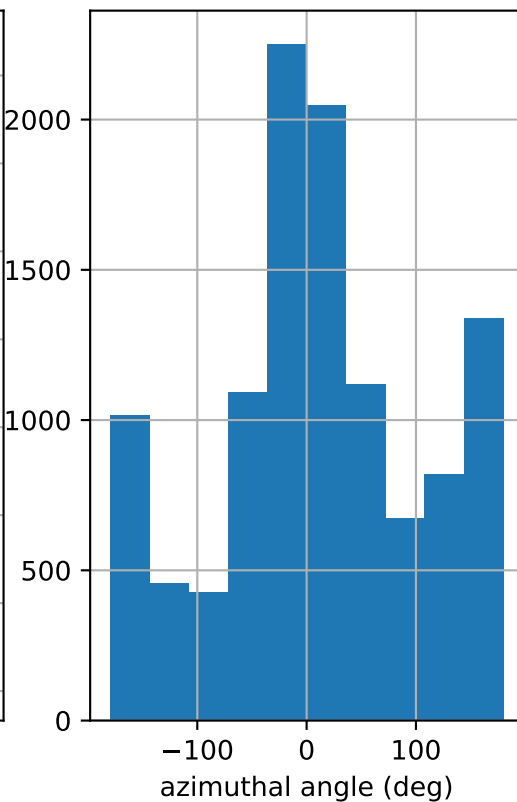
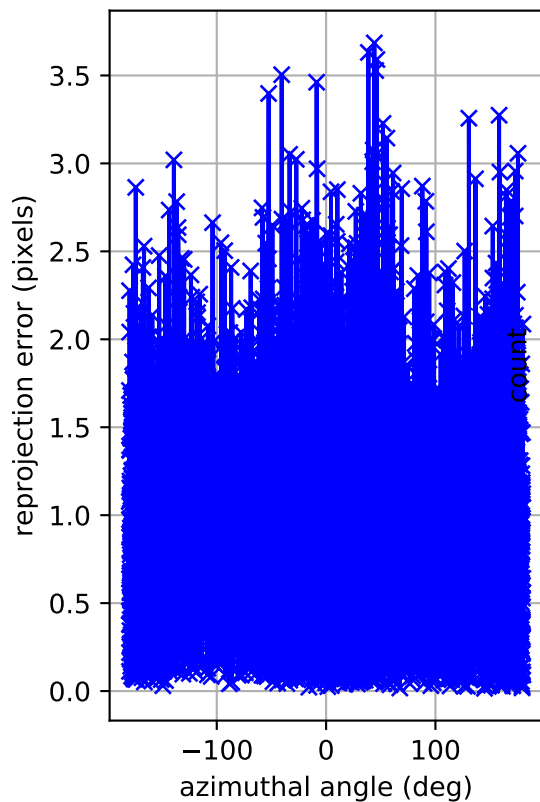
cam0: reprojection errors



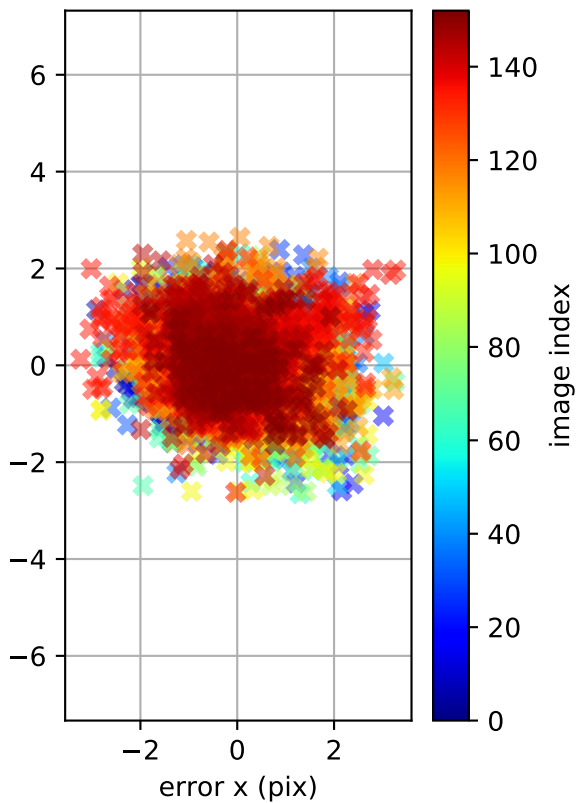
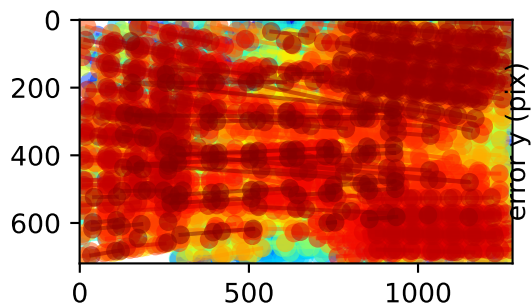
cam1: polar error



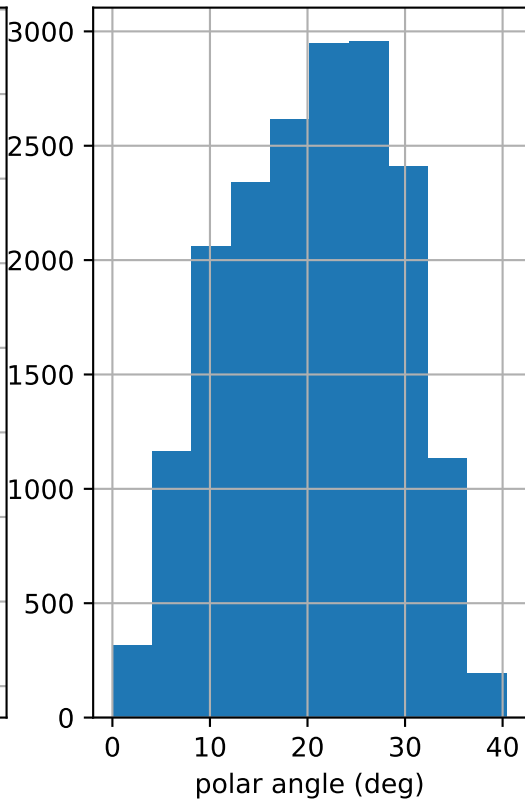
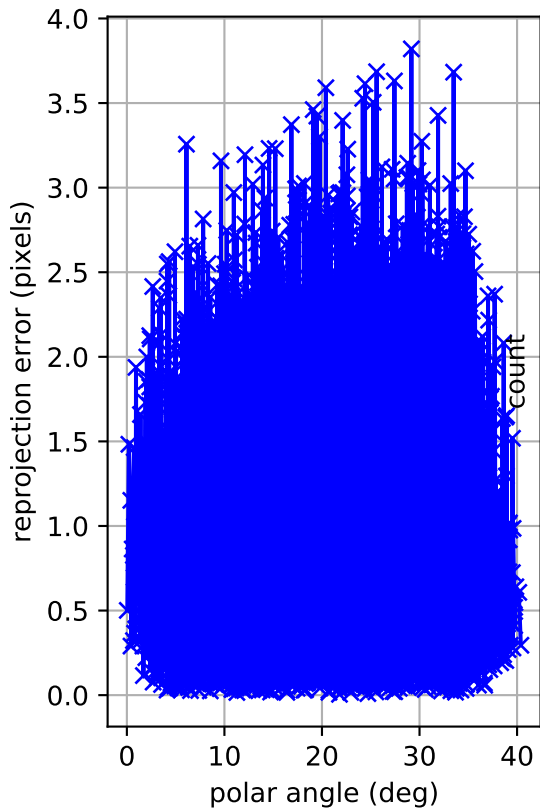
cam1: azimuthal error



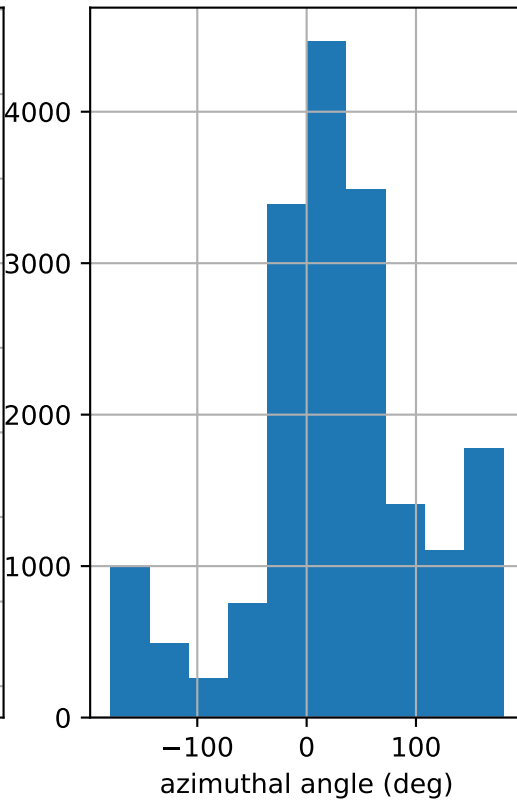
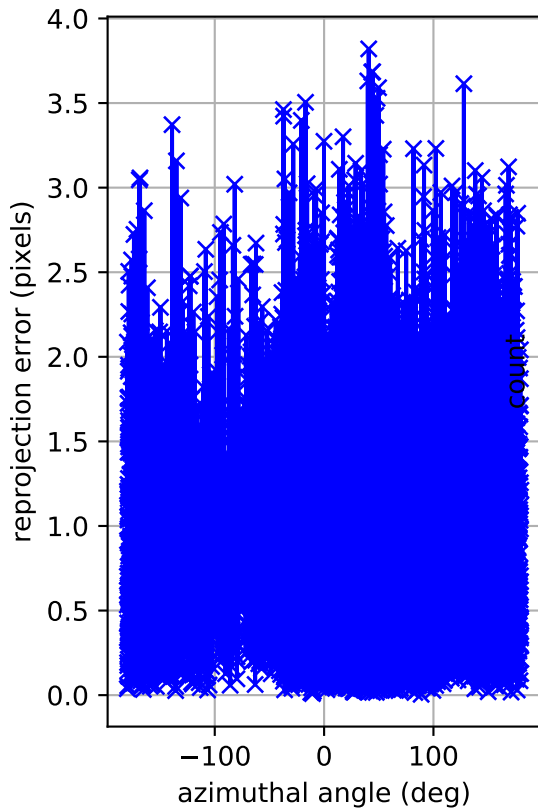
cam1: reprojection errors



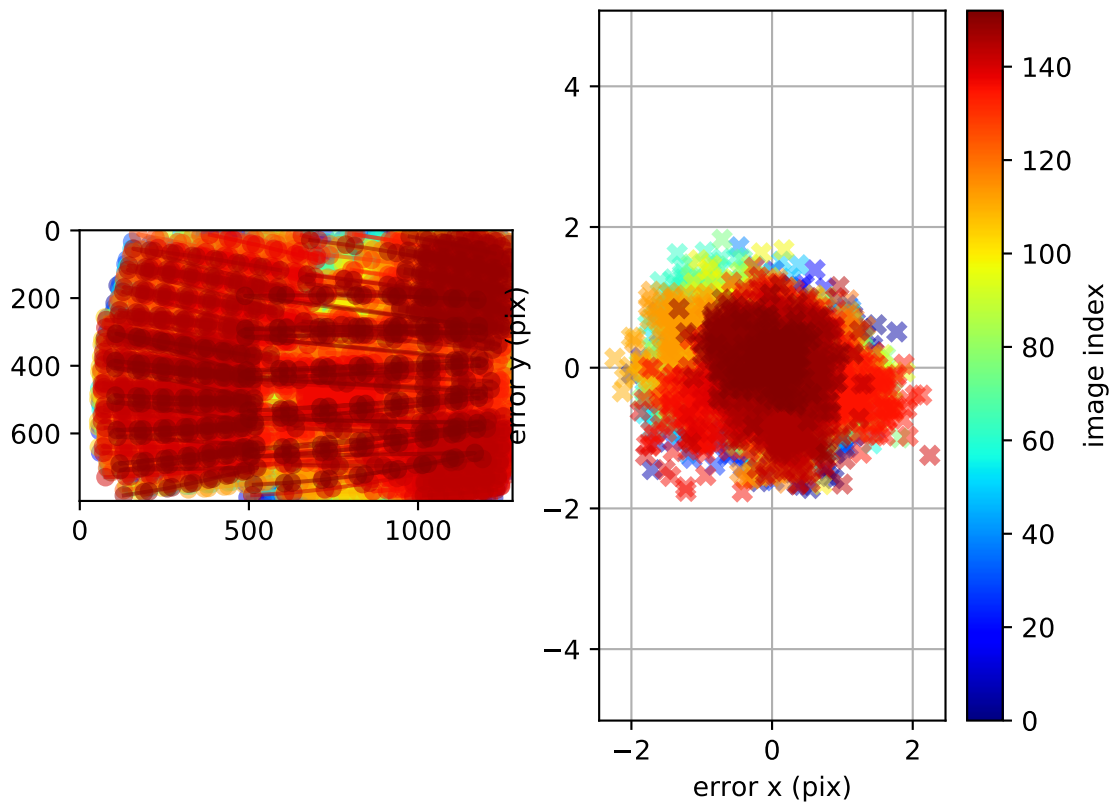
cam2: polar error



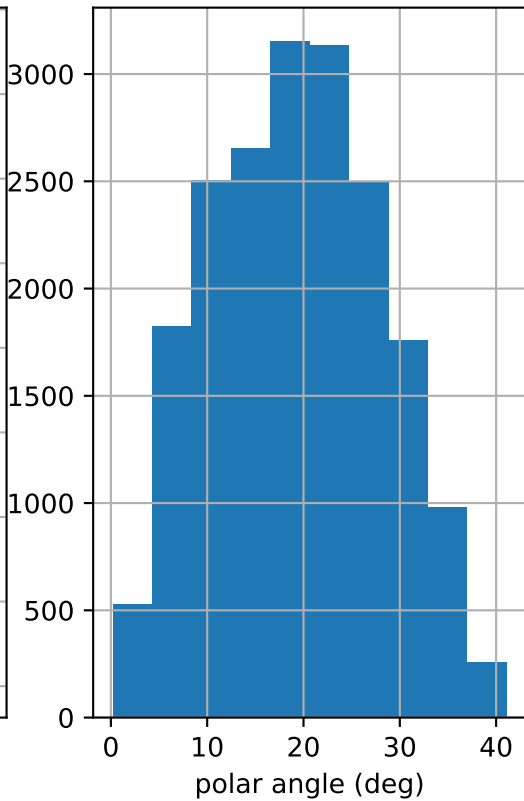
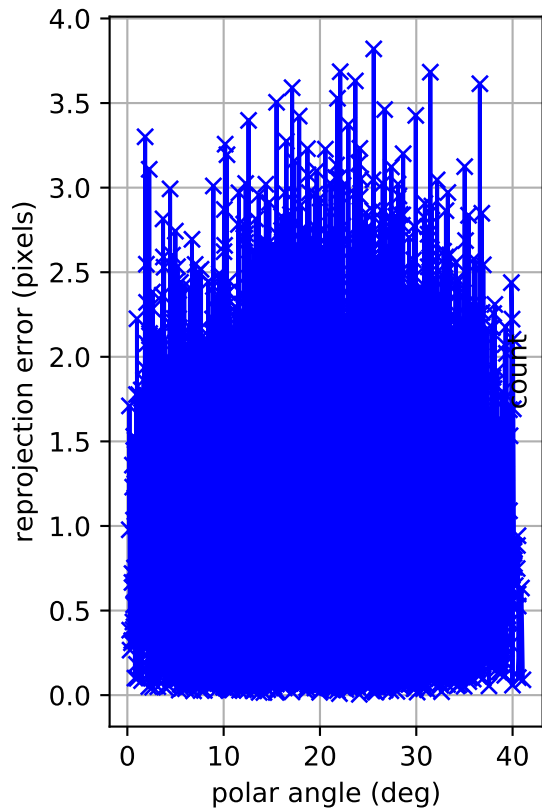
cam2: azimuthal error



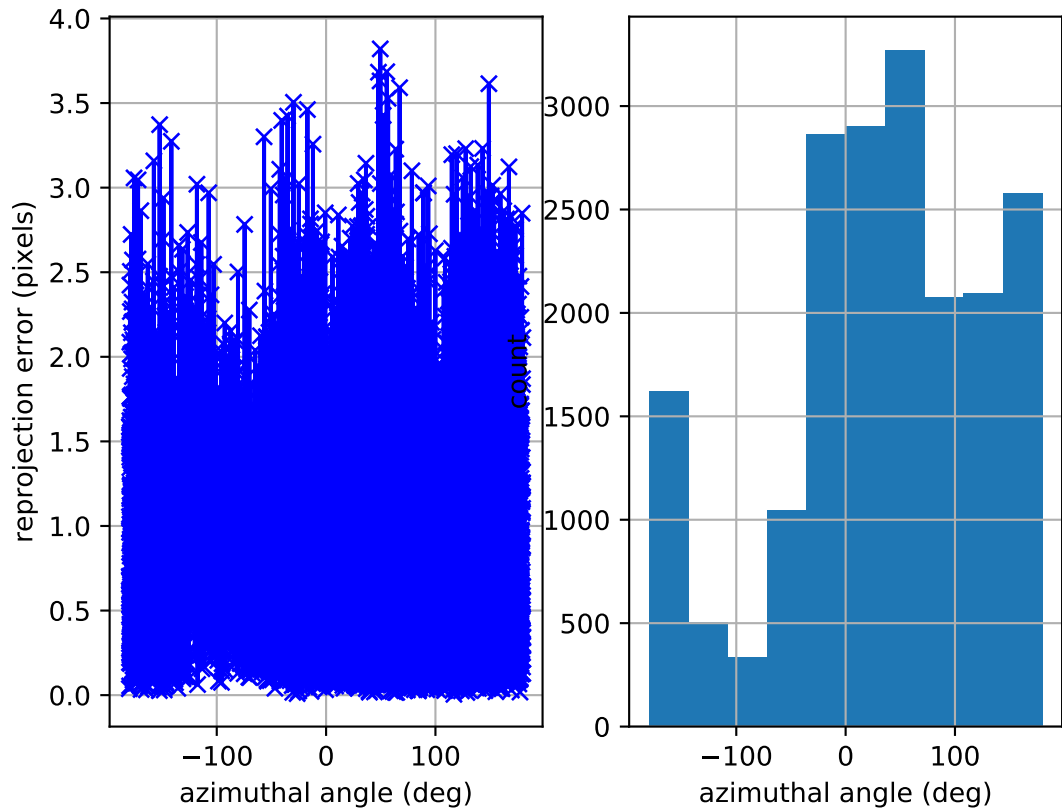
cam2: reprojection errors



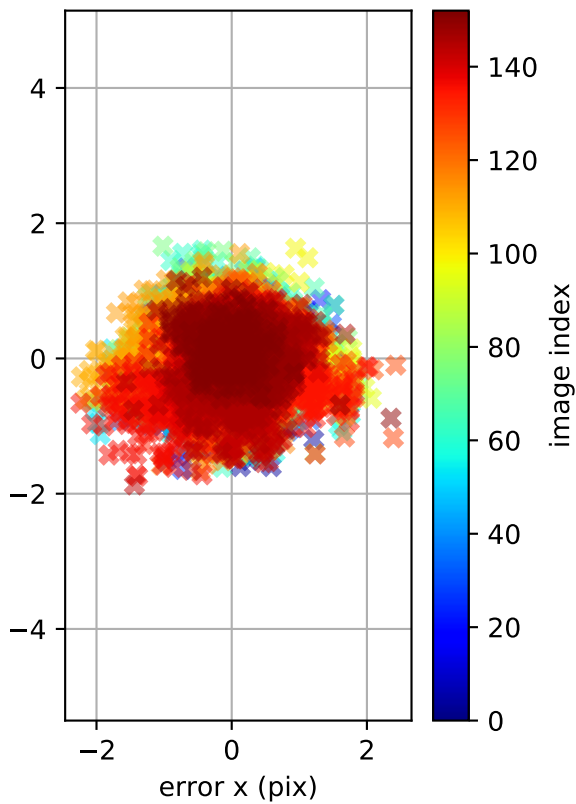
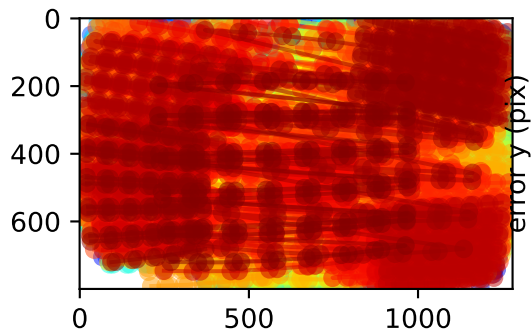
cam3: polar error



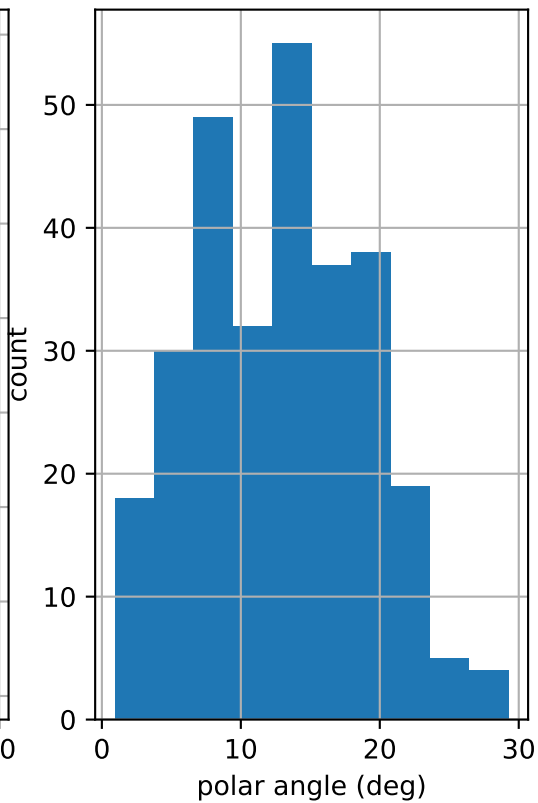
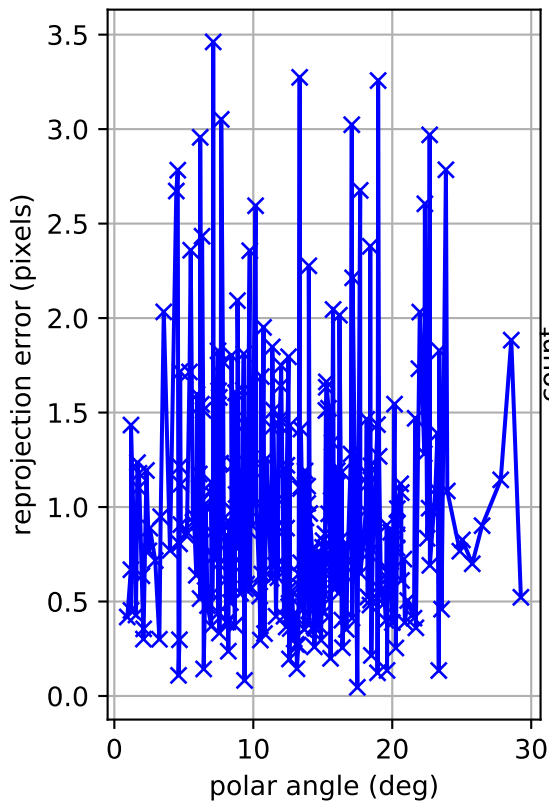
cam3: azimuthal error



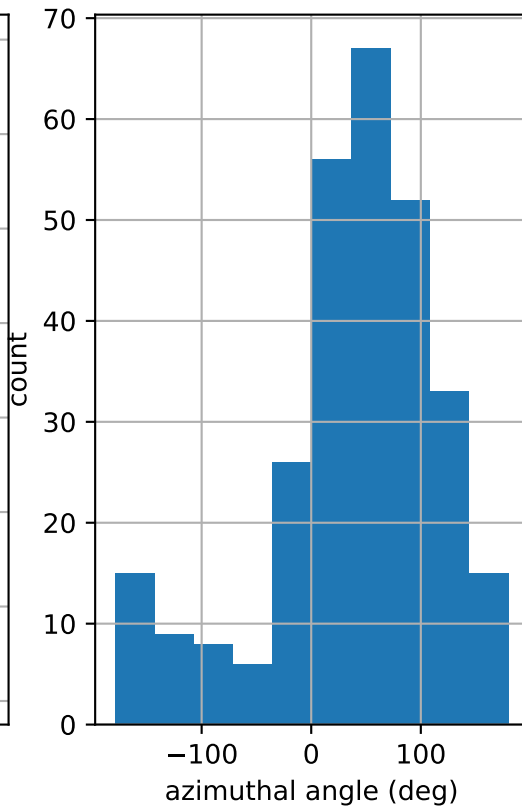
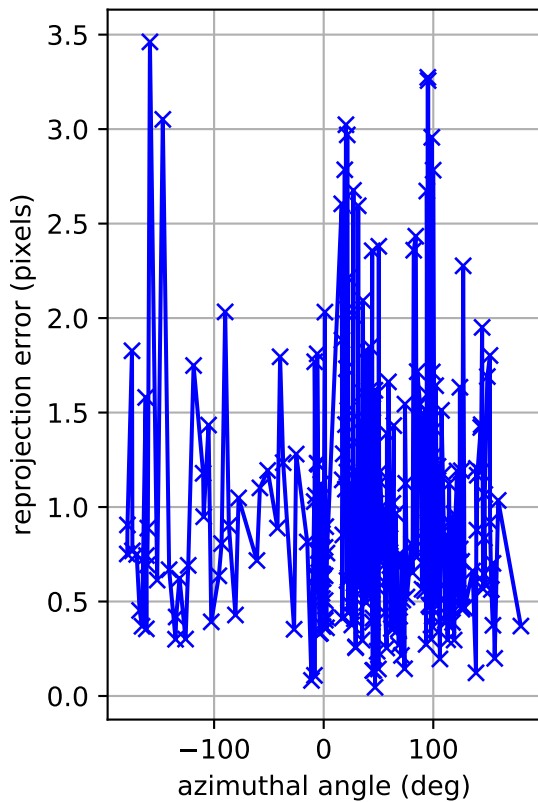
cam3: reprojection errors



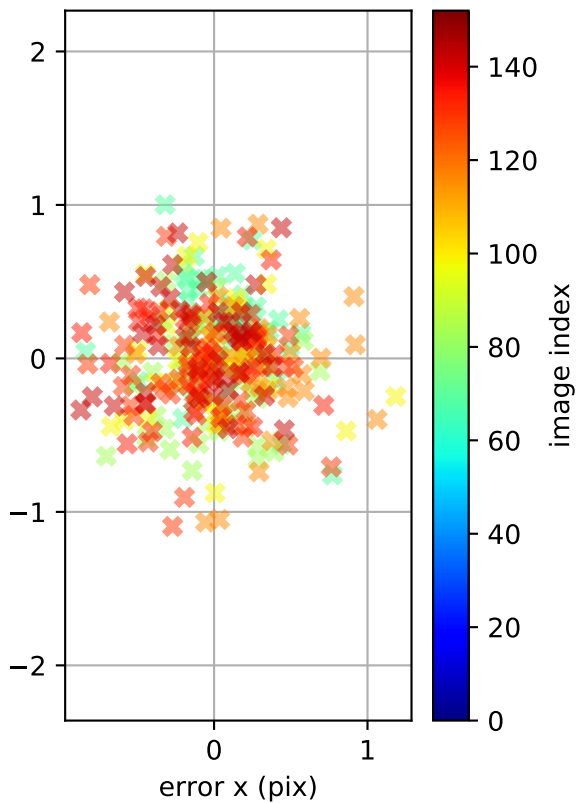
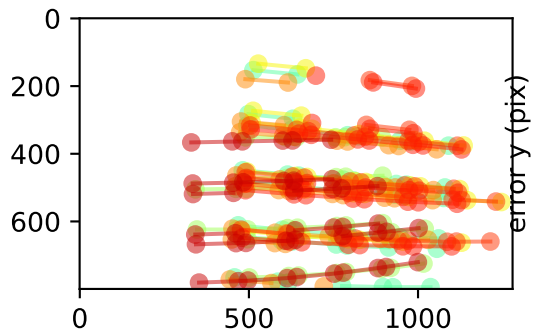
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

