

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04809944 0.08150917 0.00050312 -0.00130913] +- [0.00107731 0.00233791 0.00008926 0.00005801]
projection: [1030.92325964 1030.00315866 633.71072733 362.62458454] +- [0.15010827 0.16030167 0.0112311
0.12167385]

reprojection error: [0.000107, -0.000050] +- [0.505655, 0.433875]

cam1 (/prophesee/right/events):

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

distortion: [-0.05389102 0.08443207 0.0014159 -0.00022391] +- [0.00110262 0.00244619 0.00009179 0.00006088]
projection: [1030.97371575 1030.26872244 636.14896729 365.23145089] +- [0.15393508 0.16870078 0.00948105
0.10853878]

reprojection error: [0.000082, -0.000062] +- [0.523271, 0.468950]

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

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

distortion: [-0.3947465 0.16000757 0.00034919 0.00030134] +- [0.00055357 0.0009988 0.00005983 0.00003607]
projection: [1056.96005871 1056.44049972 674.87065908 334.82798898] +- [0.13972093 0.13889202 0.02970466
0.24255466]

reprojection error: [0.000109, -0.000137] +- [0.177462, 0.153398]

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

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

distortion: [-0.39399404 0.15502765 0.00013645 0.00081473] +- [0.0004772 0.00076335 0.00005824 0.00003933]
projection: [1051.85103241 1051.60693036 673.23662621 327.45933503] +- [0.13822693 0.14124144 0.00875351
0.24080145]

reprojection error: [0.000094, -0.000155] +- [0.192936, 0.153375]

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

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

distortion: [-0.4158847 0.18856349 0.0003964 -0.00022537] +- [0.00084608 0.00217181 0.00005909 0.00004032]
projection: [1262.77452218 1261.7398924 653.08132323 366.02630425] +- [0.13598058 0.13805974 0.01046231
0.11463278]

reprojection error: [0.000012, -0.000075] +- [0.218475, 0.203085]

baseline T_1_0:

q: [-0.00004352 0.002071 -0.00034779 0.99999779] +- [0.00010871 0.00005258 0.00004625]

t: [-0.12014495 0.00095135 0.00024308] +- [0.00003303 0.00003385 0.00013304]

baseline T_2_1:

q: [0.00026911 -0.00356681 -0.00474994 0.99998232] +- [0.00028236 0.0000579 0.00004167]

t: [0.12000597 0.06927114 0.0034483] +- [0.00002991 0.00003219 0.00012695]

baseline T_3_2:

q: [-0.00012522 0.00066967 0.00029697 0.99999972] +- [0.00033577 0.00005439 0.00003566]

t: [-0.12002625 -0.00007581 0.00052288] +- [0.00002774 0.00002798 0.0001172]

baseline T_4_3:

q: [0.00204297 0.00172697 0.00035157 0.99999636] +- [0.00028628 0.00004024 0.00003436]

t: [0.08886835 0.00622817 0.00279058] +- [0.00002575 0.00002654 0.00010962]

Target configuration

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Type: aprilgrid

Tags:

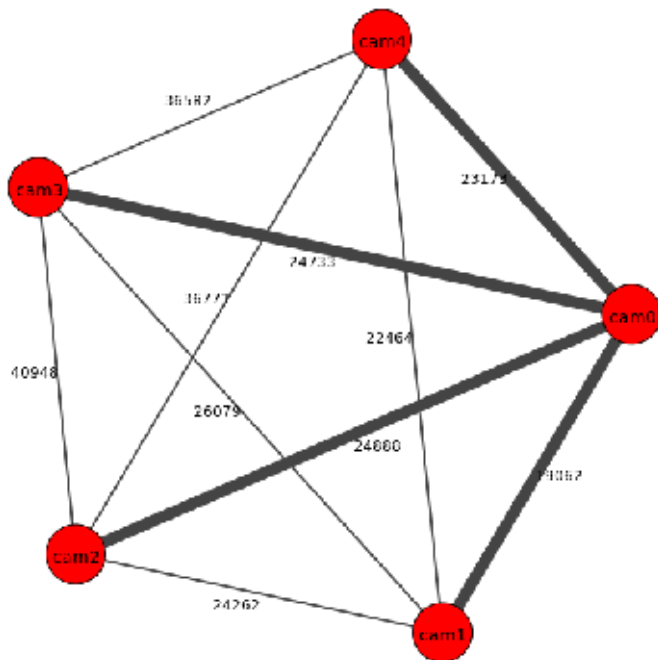
Rows: 5

Cols: 7

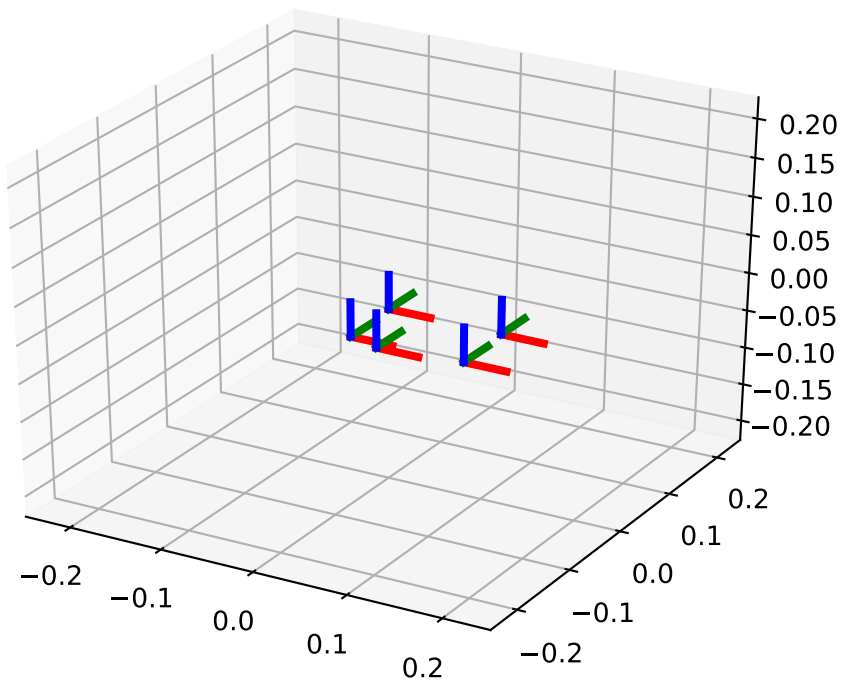
Size: 0.04 [m]

Spacing 0.01 [m]

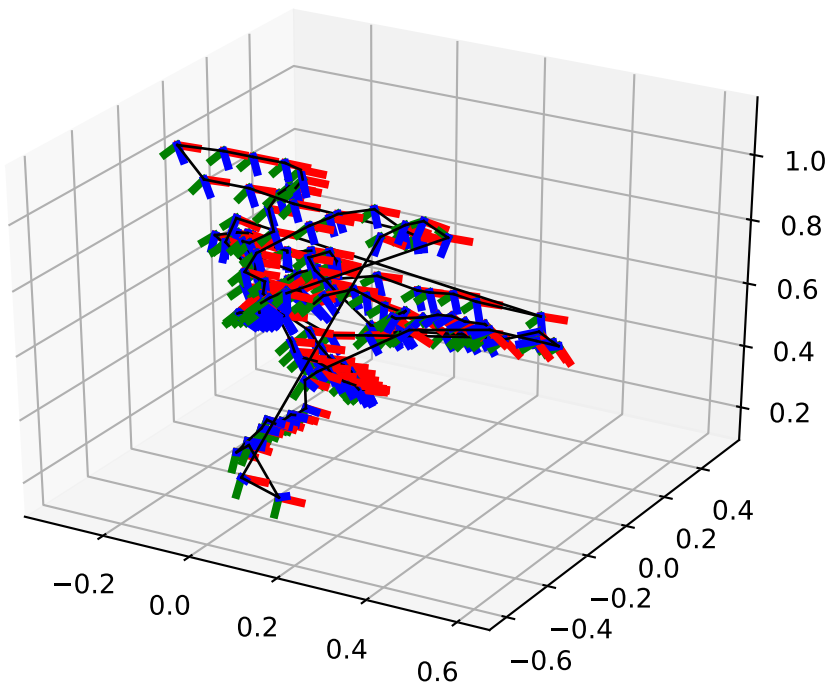
Inter-camera observations graph (edge weight=#mutual obs.)



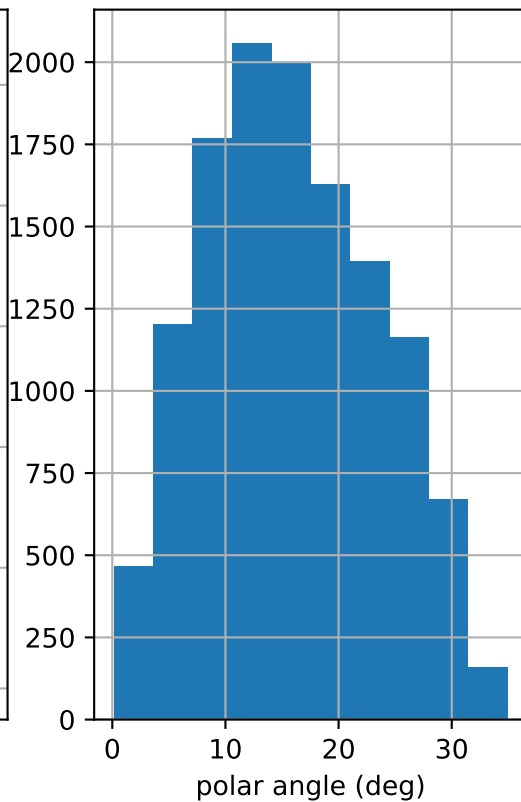
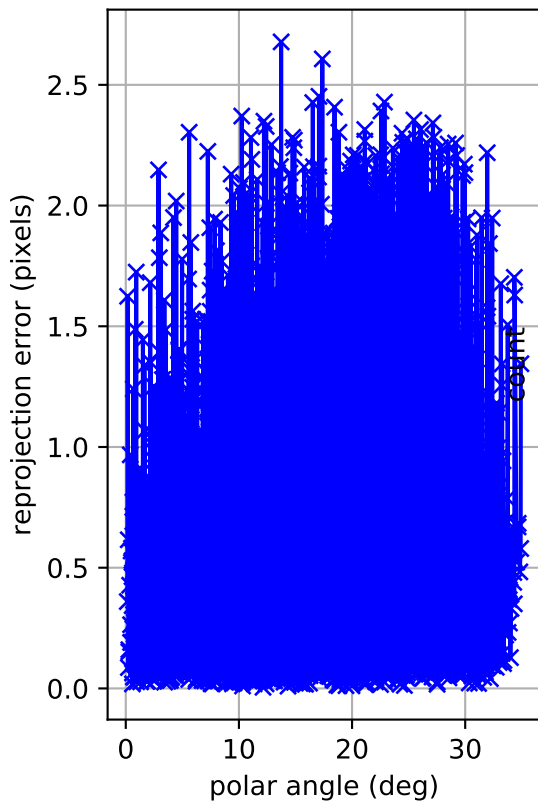
camera system



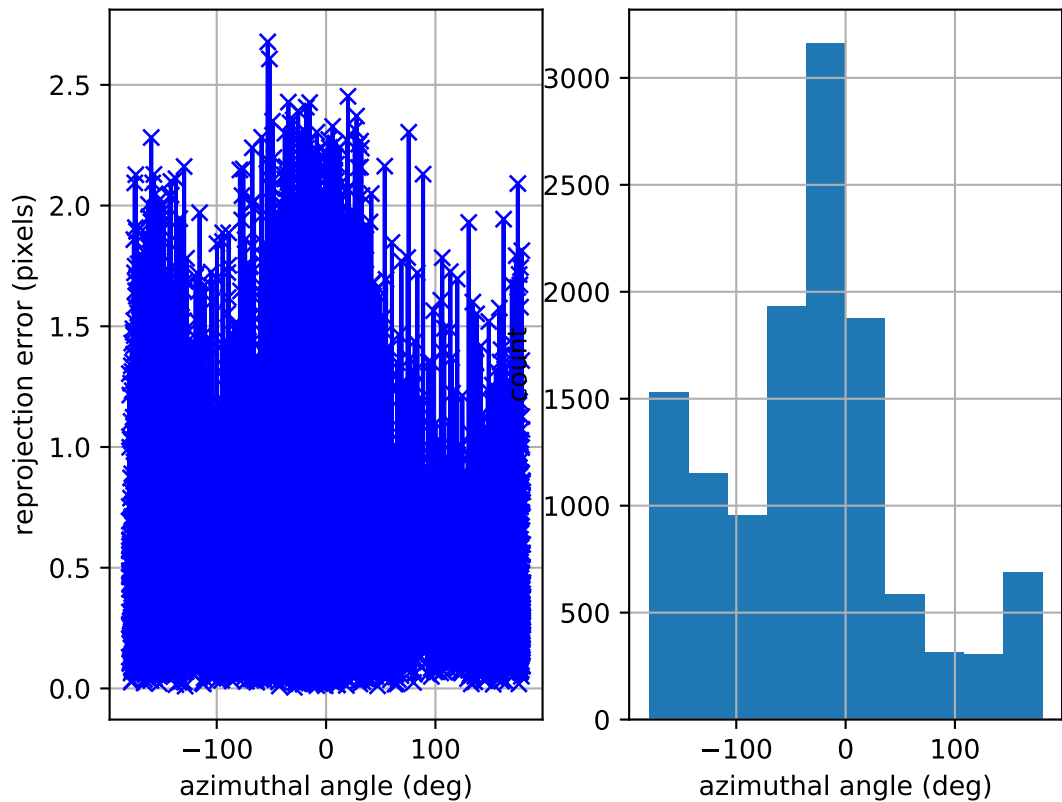
cam0: estimated poses



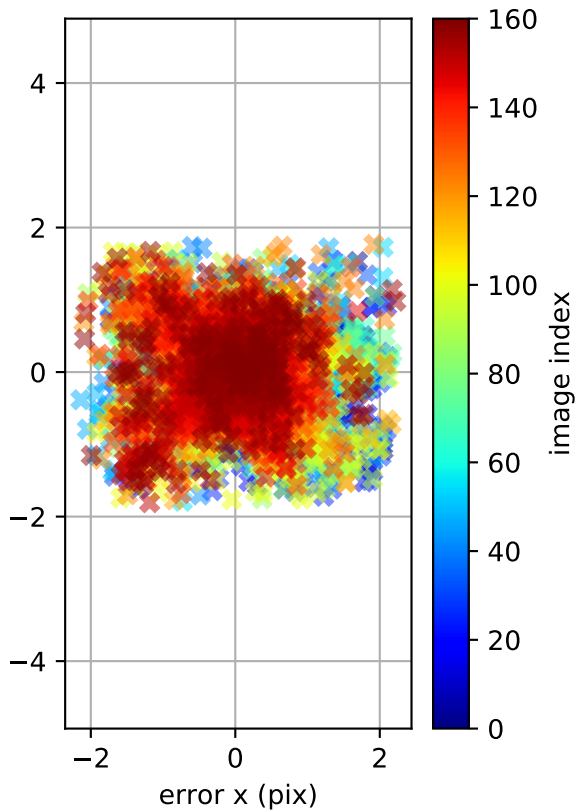
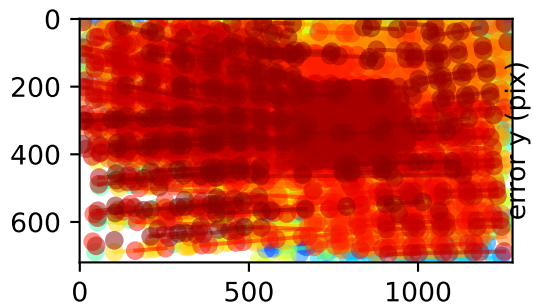
cam0: polar error



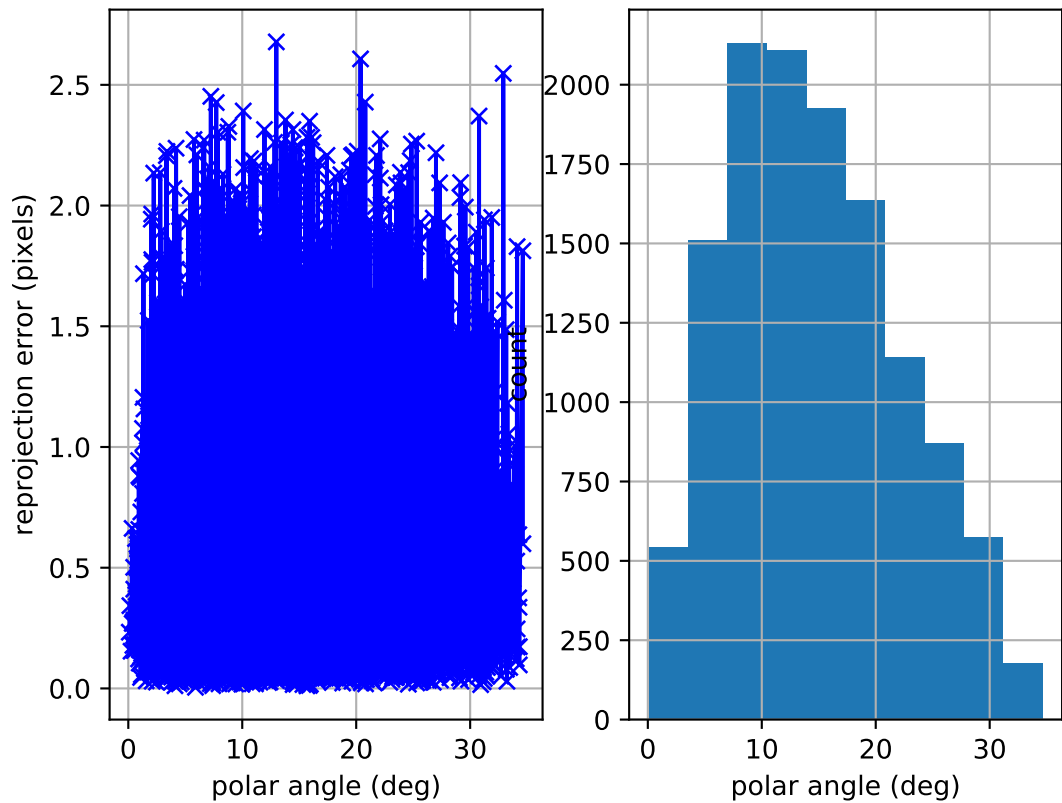
cam0: azimuthal error



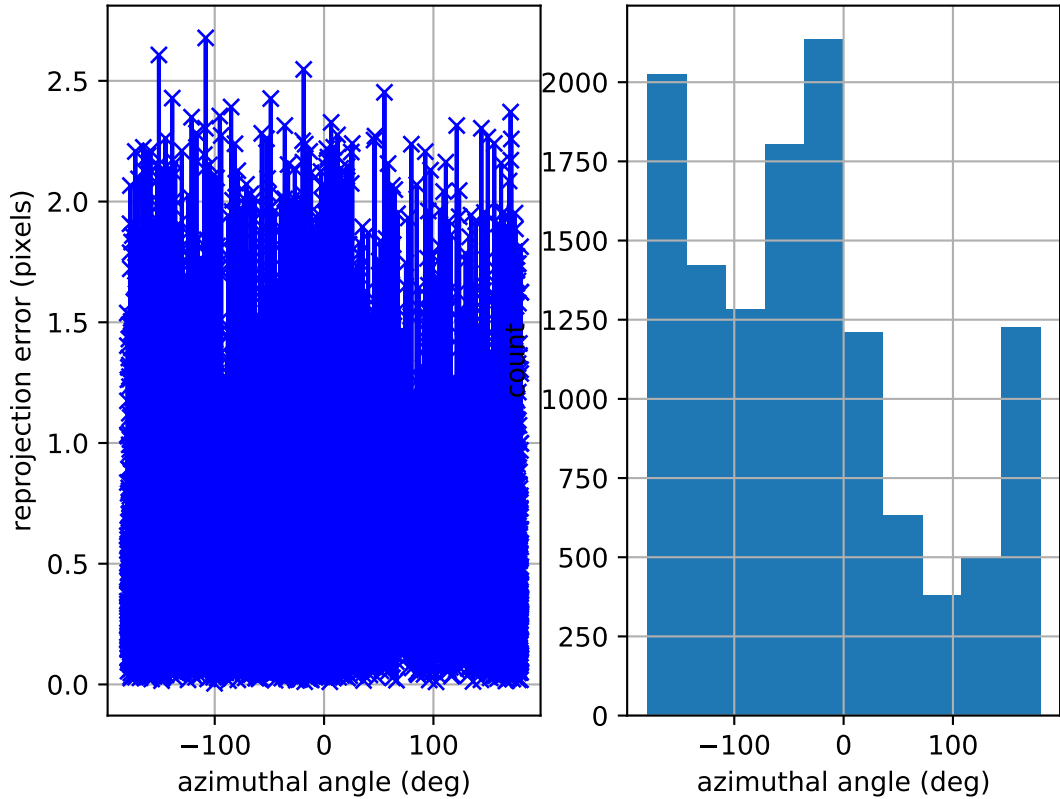
cam0: reprojection errors



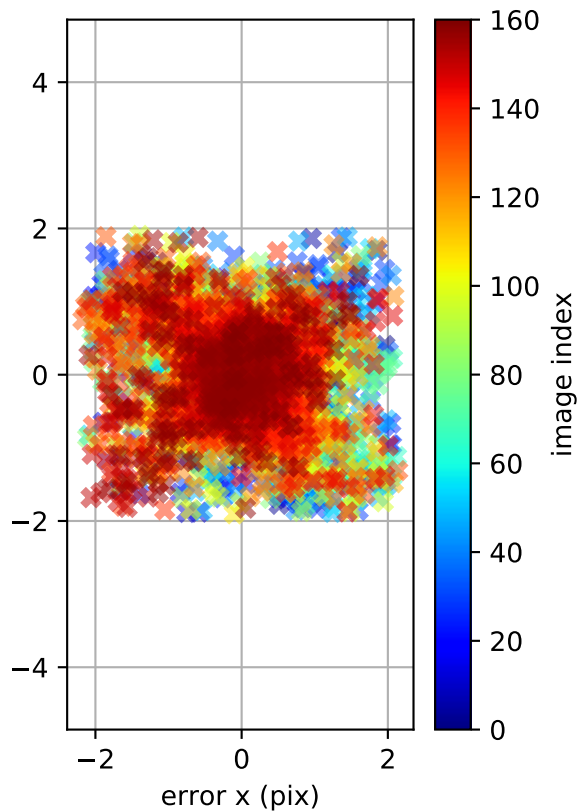
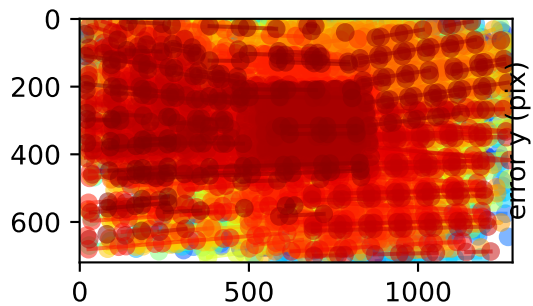
cam1: polar error



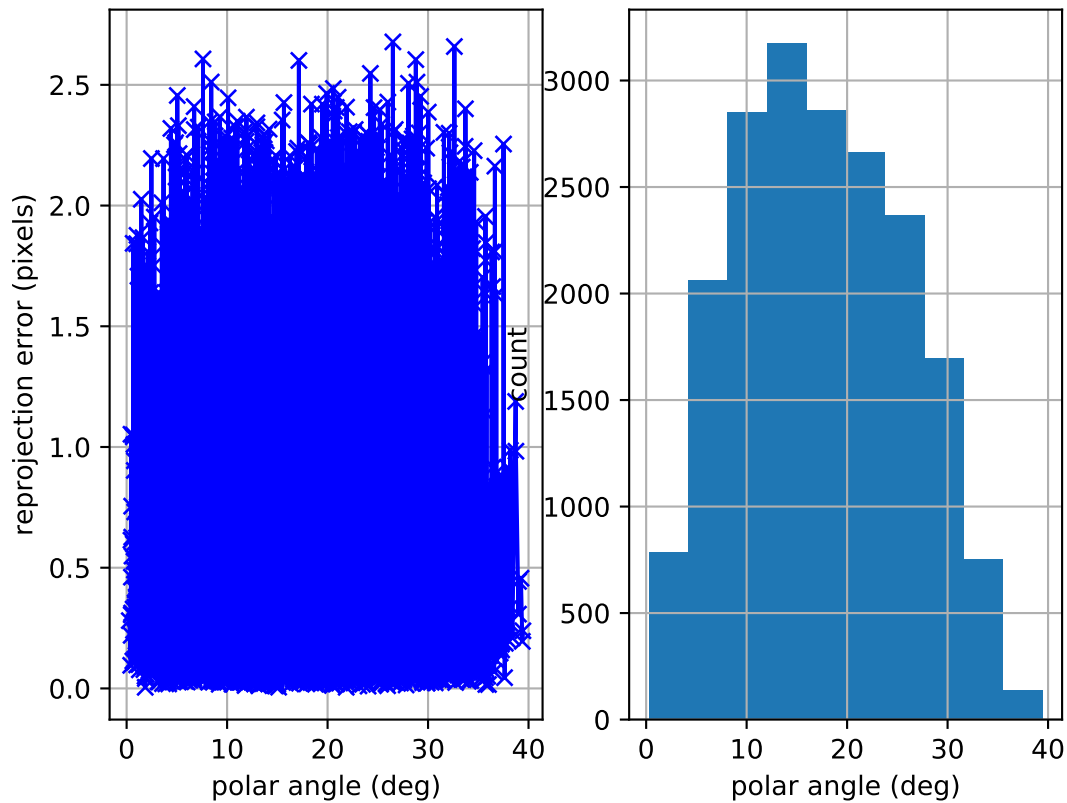
cam1: azimuthal error



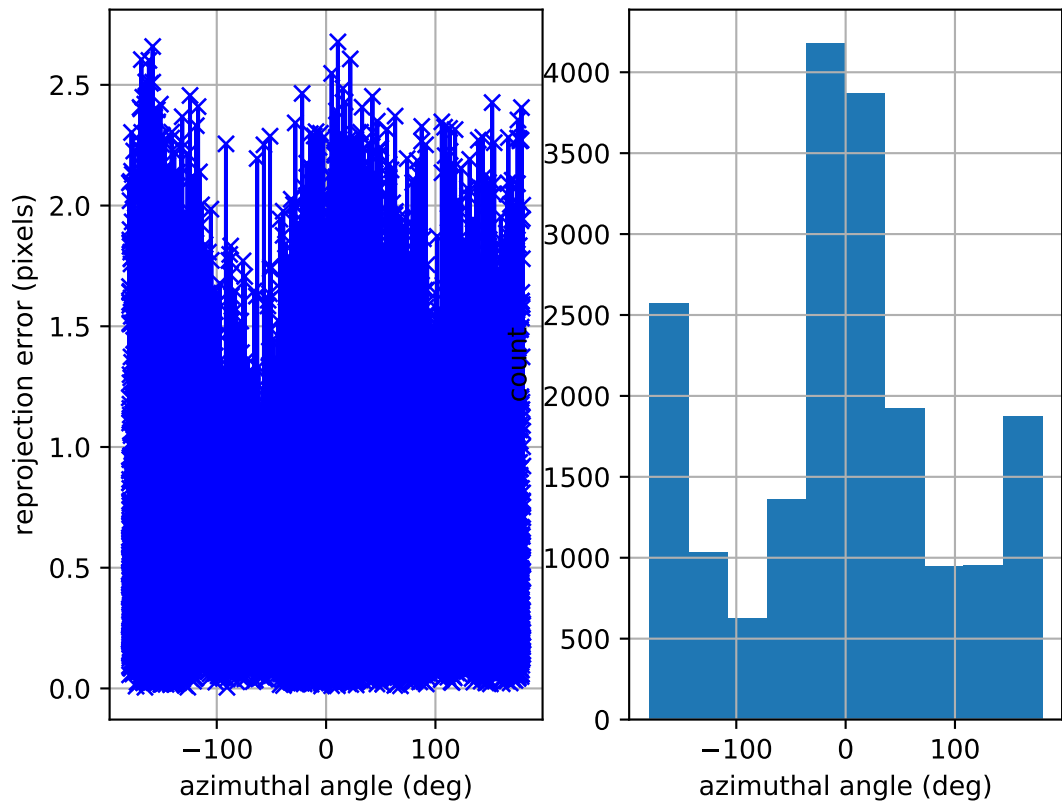
cam1: reprojection errors



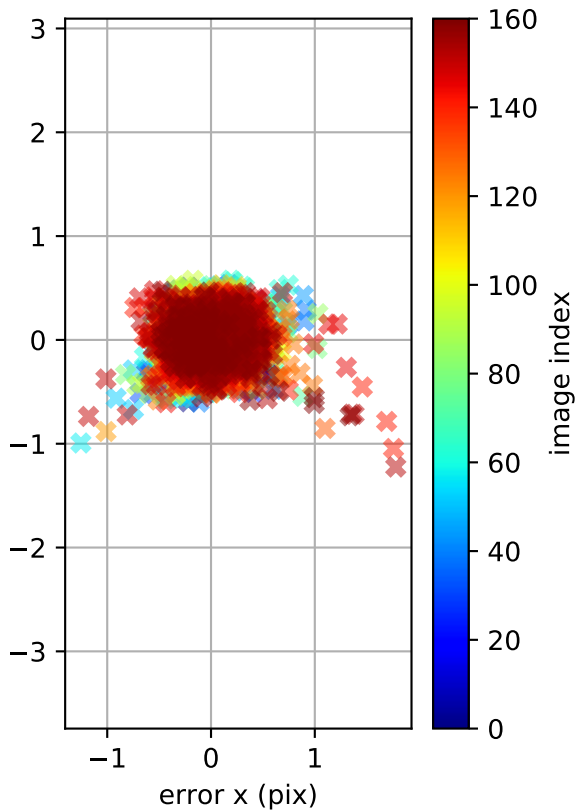
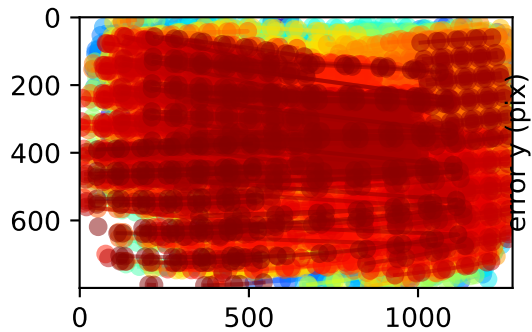
cam2: polar error



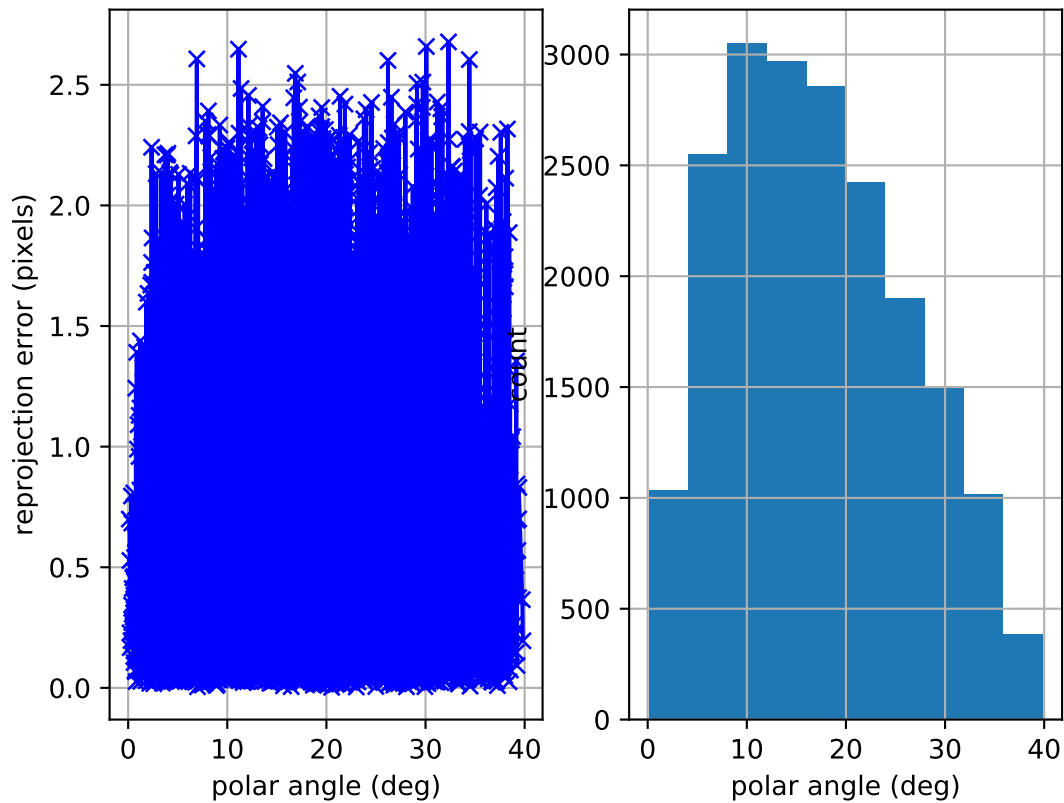
cam2: azimuthal error



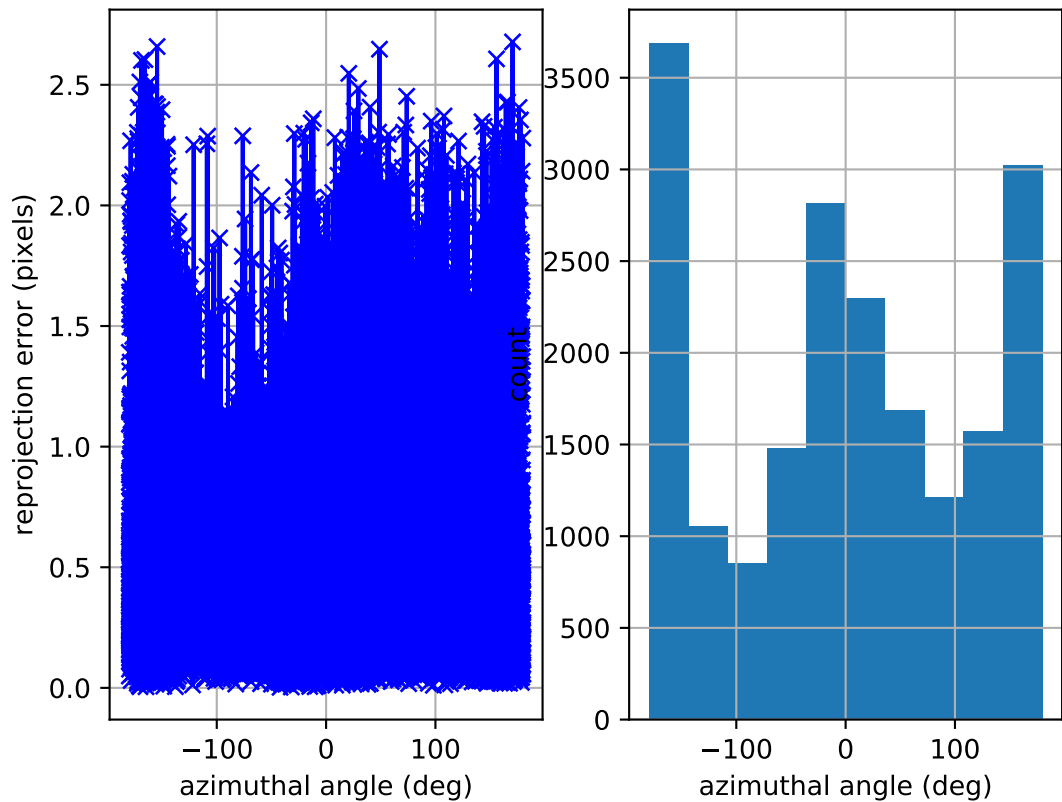
cam2: reprojection errors



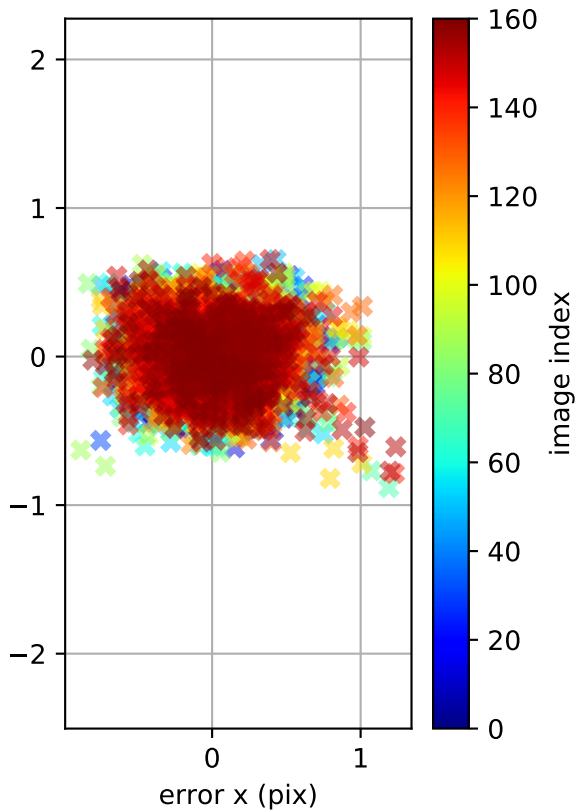
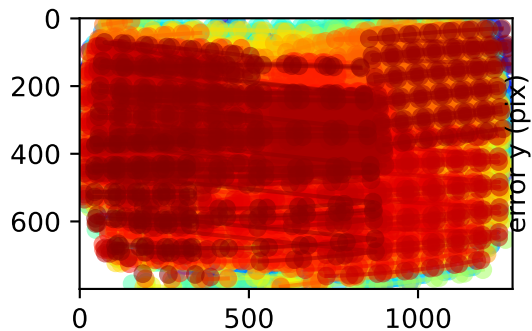
cam3: polar error



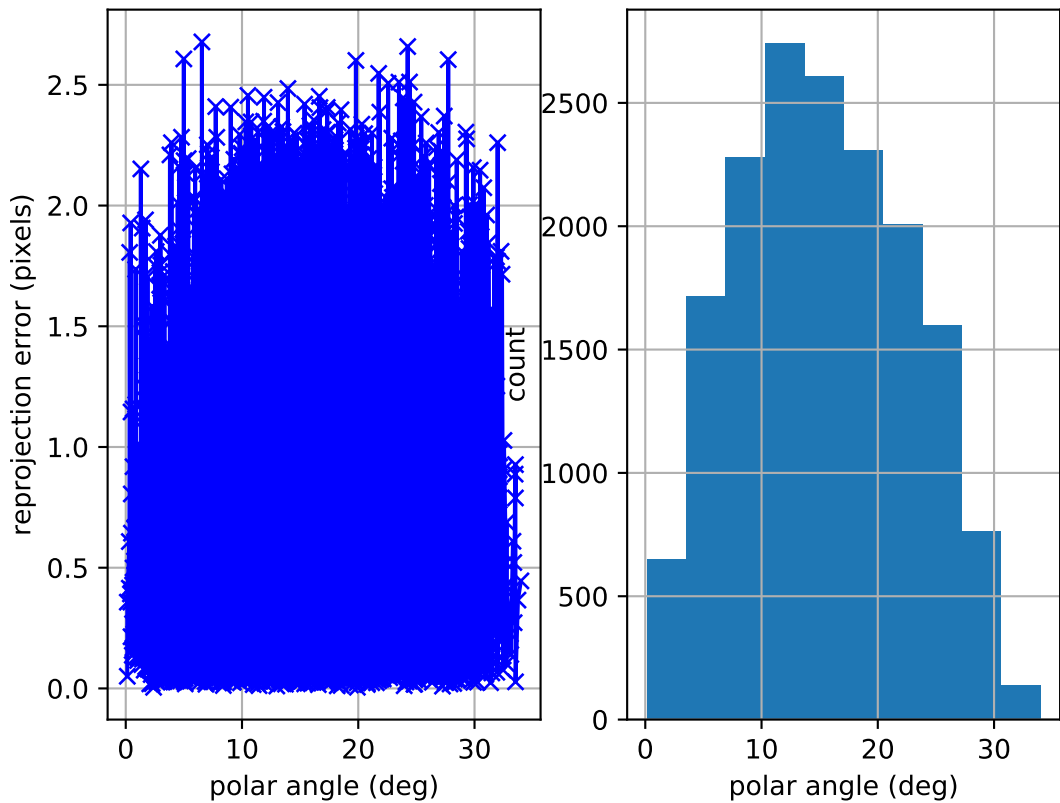
cam3: azimuthal error



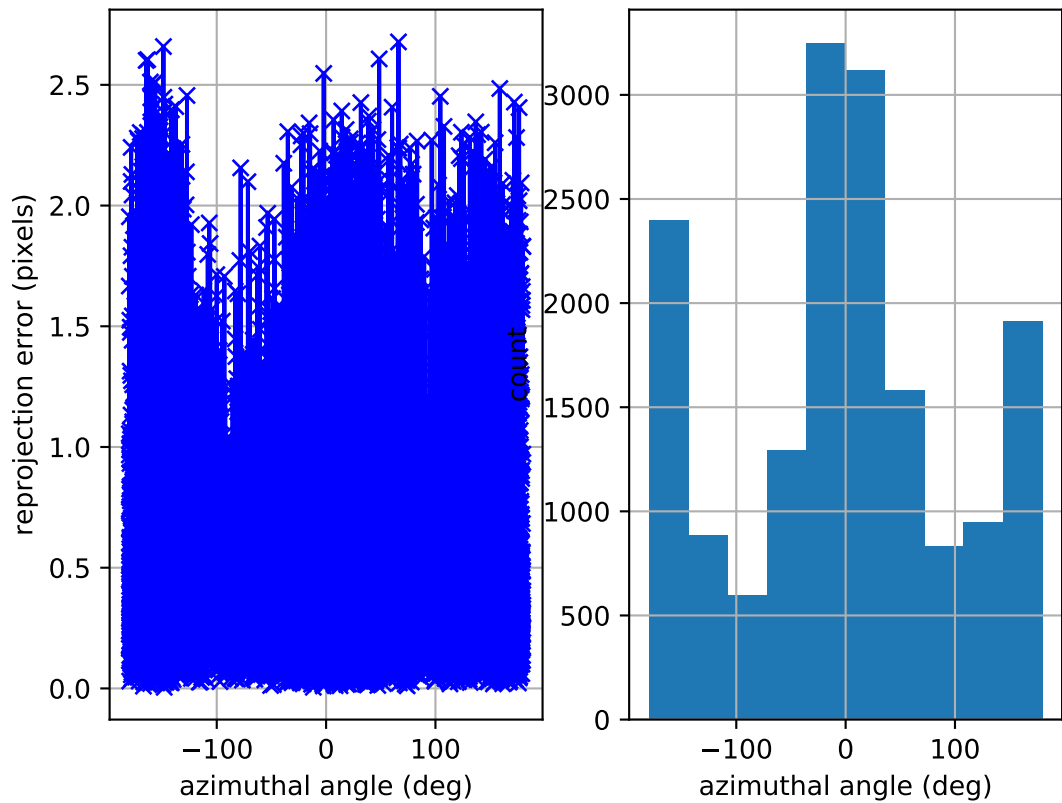
cam3: reprojection errors



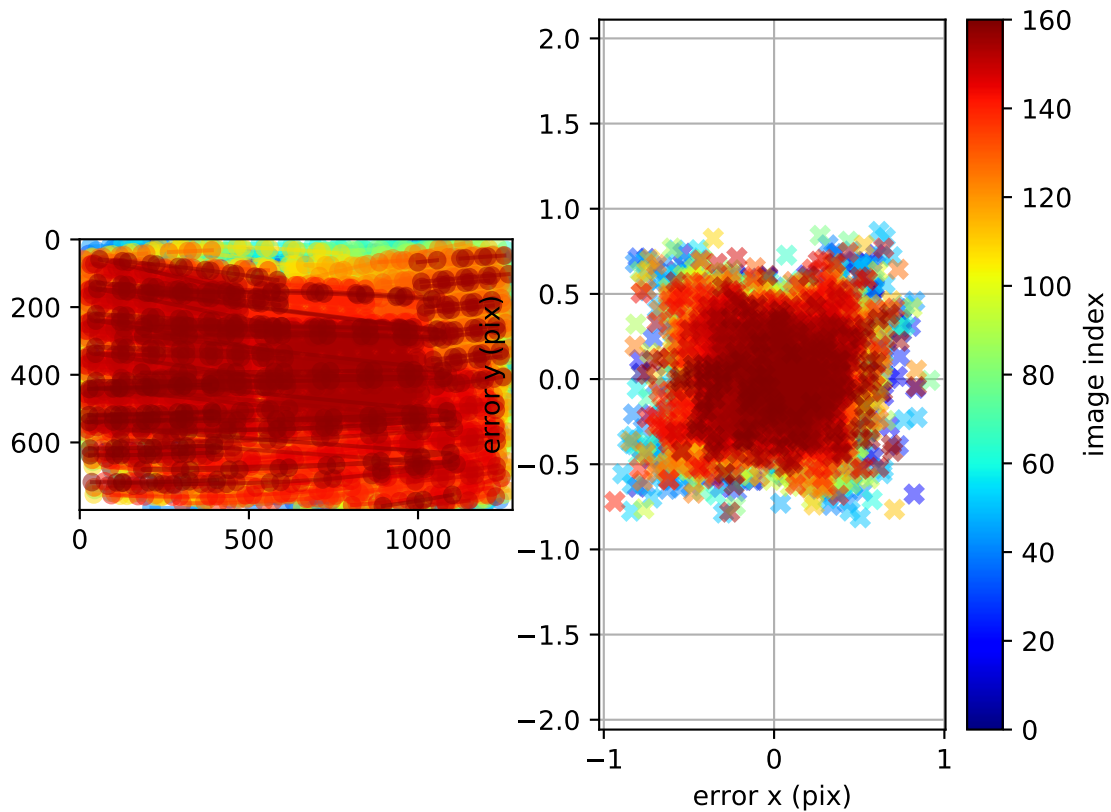
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

