

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.05023217 0.08541707 -0.00033655 -0.00022546] +- [0.0012458 0.00304937 0.00008624 0.00005595]
projection: [1033.70021173 1032.9662337 636.7474923 359.68456239] +- [0.18324443 0.18001496 0.00518548 0.07535926]

reprojection error: [0.000228, -0.000047] +- [0.646585, 0.570415]

cam1 (/prophesee/right/events):

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

distortion: [-0.0539046 0.08042954 0.00126327 0.00086381] +- [0.00120095 0.00273633 0.00008551 0.00006962]
projection: [1033.2105171 1033.06220678 636.19389465 366.42827025] +- [0.21022319 0.20072944 0.00908939 0.07260106]

reprojection error: [0.000175, -0.000119] +- [0.677229, 0.590816]

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

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

distortion: [-0.39707241 0.16485734 -0.0000434 0.00039343] +- [0.00055905 0.00103909 0.00005593 0.00003337]
projection: [1059.49311341 1059.65325724 676.03919116 334.61238256] +- [0.13552998 0.13529175 0.00950538 0.26113629]

reprojection error: [0.000213, -0.000179] +- [0.212373, 0.177109]

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

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

distortion: [-0.39383106 0.15599943 -0.000226 0.00112849] +- [0.00048564 0.00076441 0.00005361 0.00003978]
projection: [1053.8439615 1054.60023766 672.4009653 327.43070741] +- [0.1484341 0.14450923 0.01148039 0.27406511]

reprojection error: [0.000248, -0.000190] +- [0.242276, 0.190770]

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

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

distortion: [-0.41891406 0.19552524 0.00008314 -0.00018504] +- [0.00080369 0.00208228 0.00005823 0.00003822]
projection: [1265.75819772 1265.78107026 654.43045638 365.94009707] +- [0.14791225 0.14645883 0.00705058 0.17092732]

reprojection error: [0.000126, -0.000177] +- [0.216767, 0.190787]

baseline T_1_0:

q: [-0.00158763 0.00201814 -0.00029796 0.99999666] +- [0.00010666 0.00008083 0.00004891]

t: [-0.12013992 0.0007929 -0.00041032] +- [0.00004283 0.00003991 0.00014336]

baseline T_2_1:

q: [0.00045654 -0.00408326 -0.00485045 0.9999798] +- [0.00026579 0.00007384 0.00004487]

t: [0.12027705 0.06925807 0.00397008] +- [0.00003812 0.00003521 0.0001278]

baseline T_3_2:

q: [-0.00031674 -0.00024622 0.00037275 0.99999985] +- [0.00036748 0.00005847 0.00003927]

t: [-0.12004218 -0.00009424 0.00058822] +- [0.00002938 0.00002701 0.00009472]

baseline T_4_3:

q: [0.00218062 0.00257621 0.00026865 0.99999427] +- [0.00035545 0.00005499 0.00003878]

t: [0.08889515 0.00619263 0.00290837] +- [0.00002806 0.00002471 0.00009071]

Target configuration

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Type: aprilgrid

Tags:

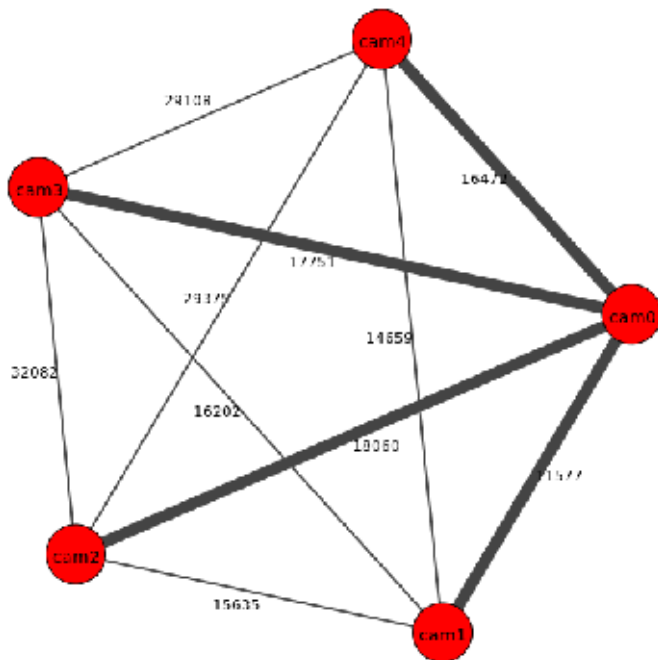
Rows: 5

Cols: 7

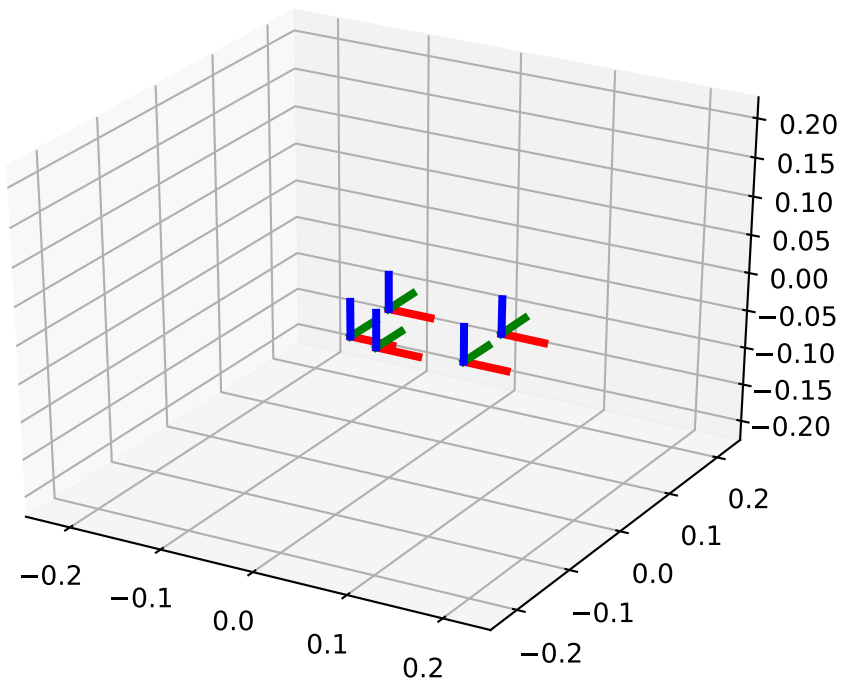
Size: 0.04 [m]

Spacing 0.01 [m]

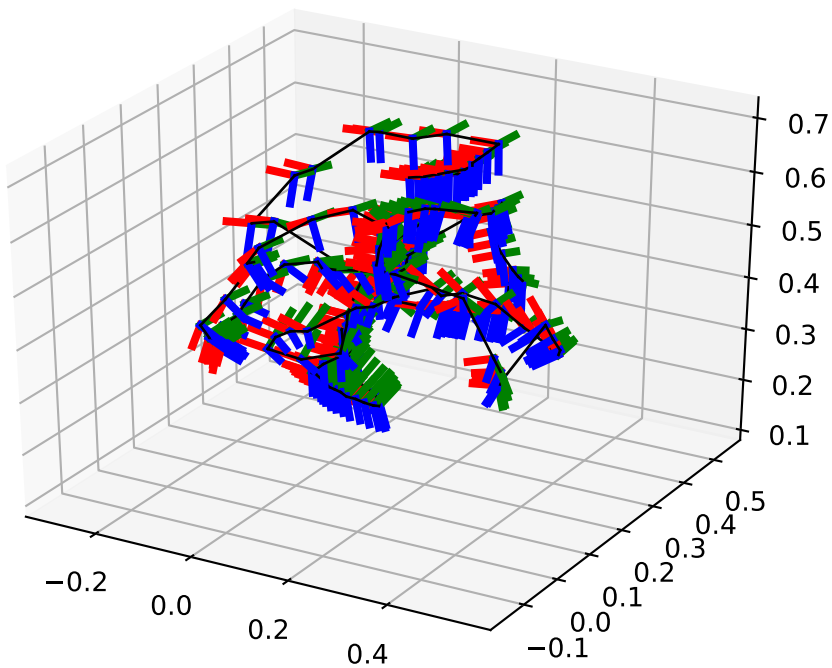
Inter-camera observations graph (edge weight=#mutual obs.)



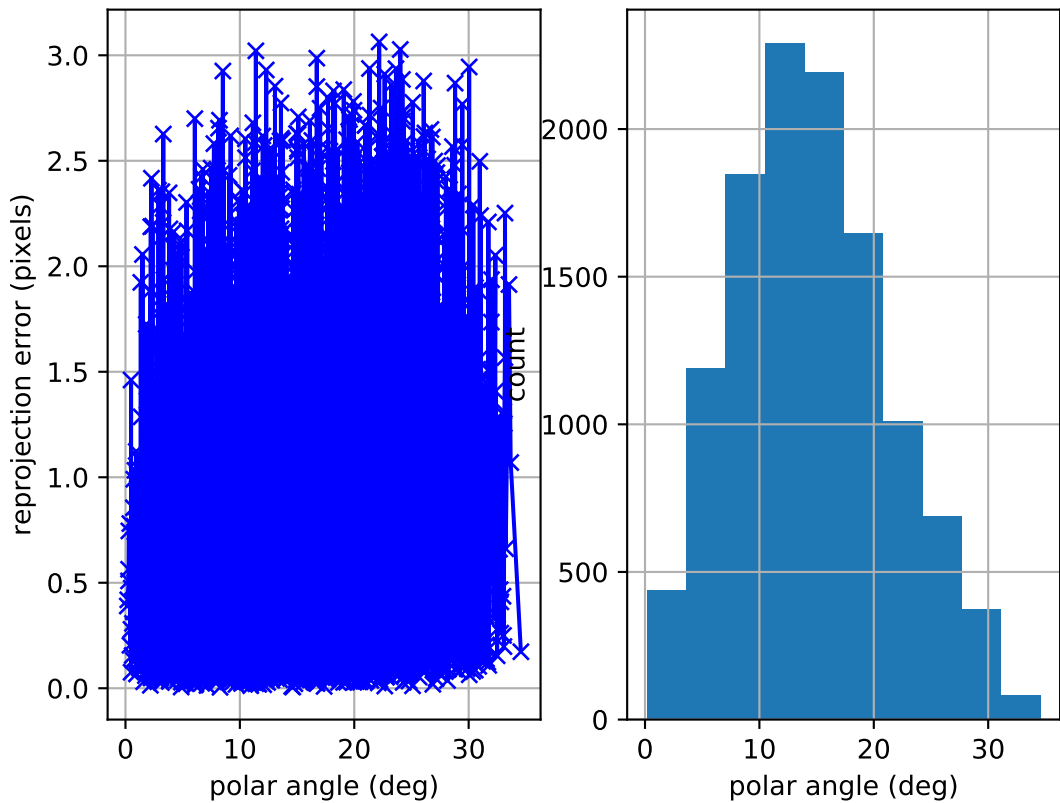
camera system



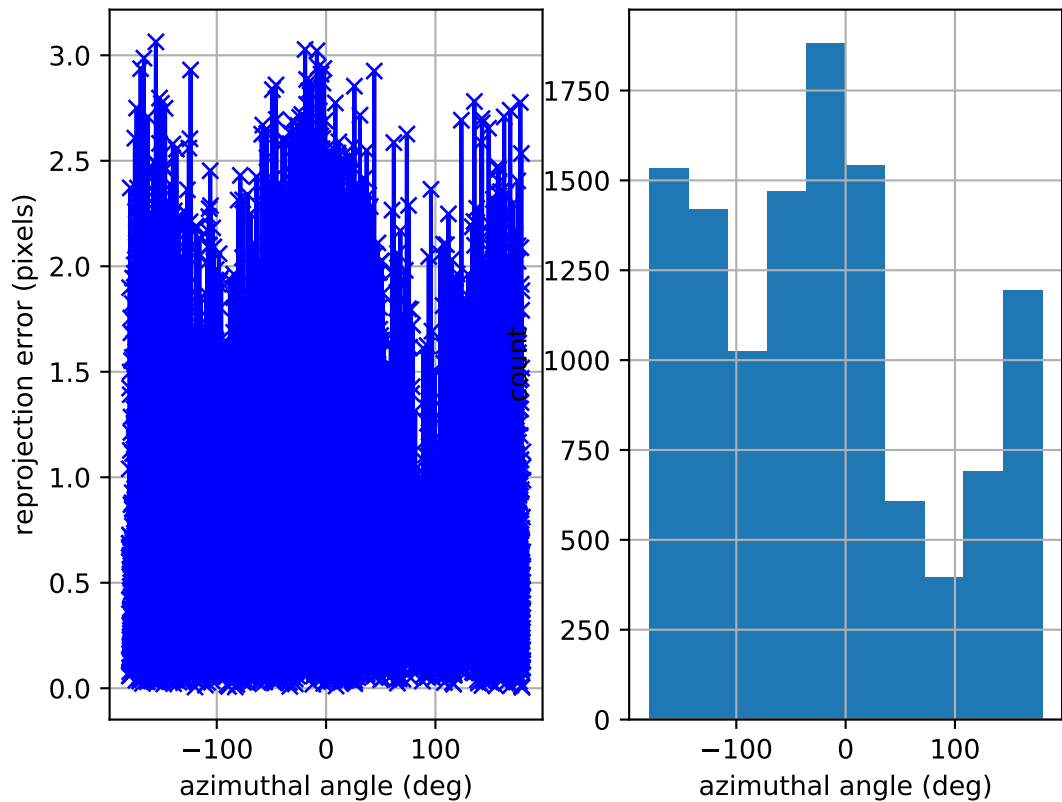
cam0: estimated poses



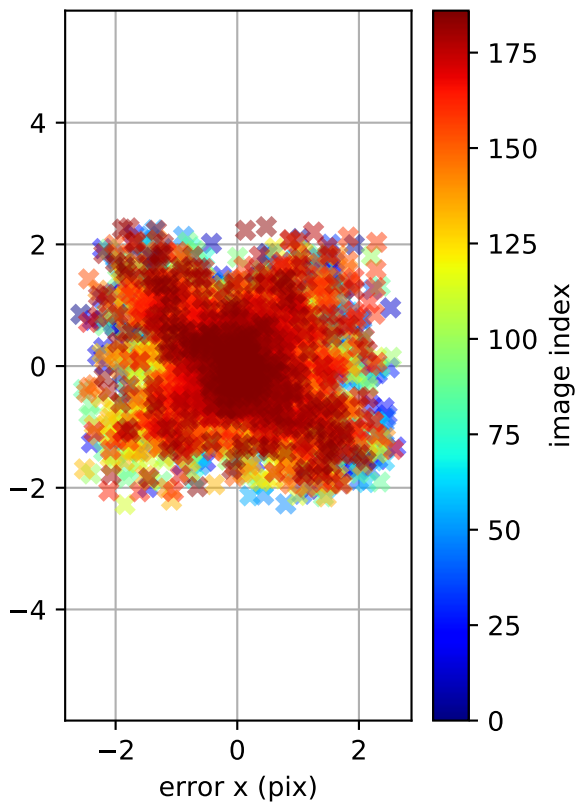
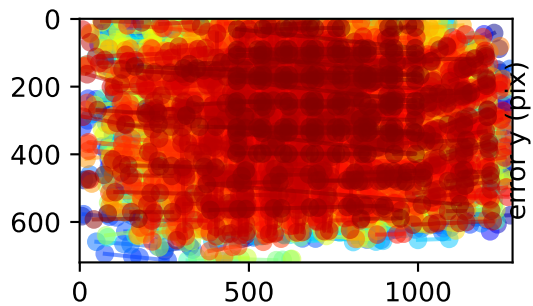
cam0: polar error



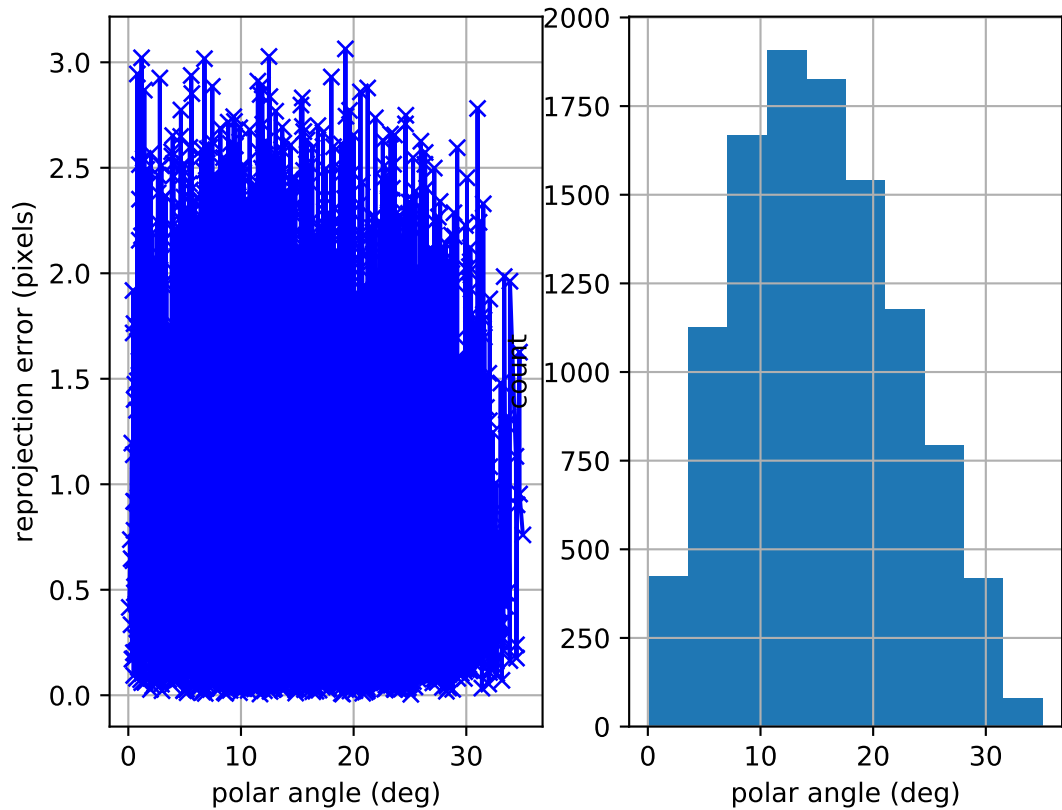
cam0: azimuthal error



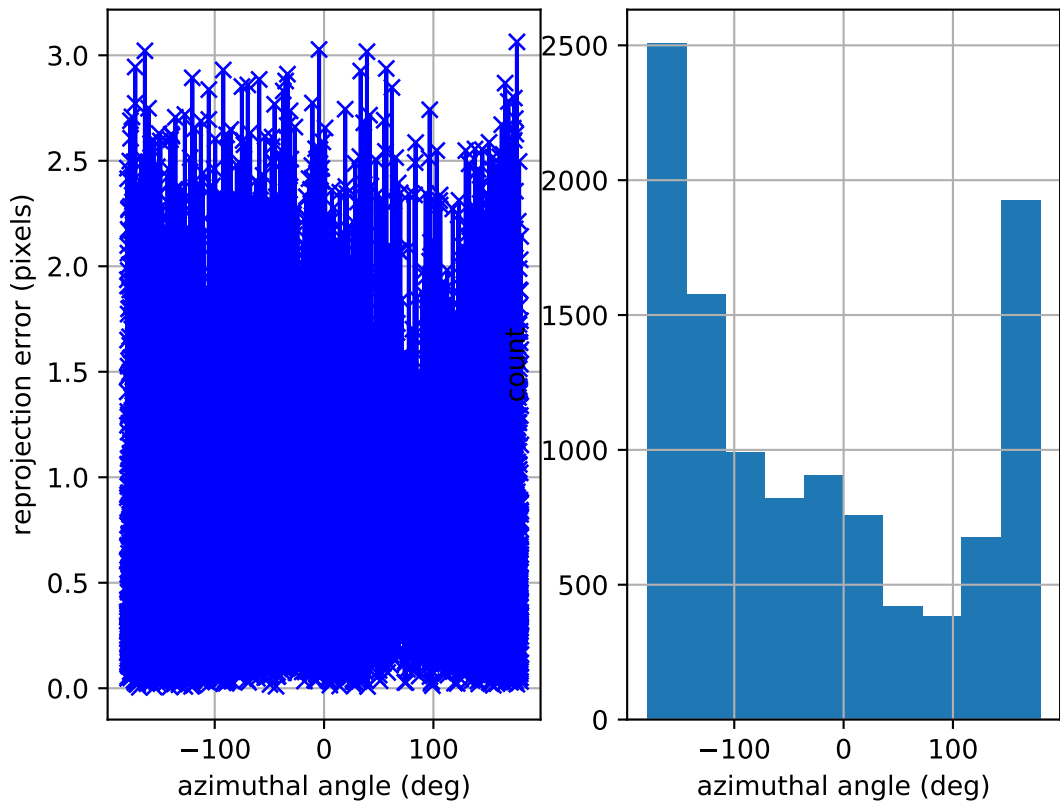
cam0: reprojection errors



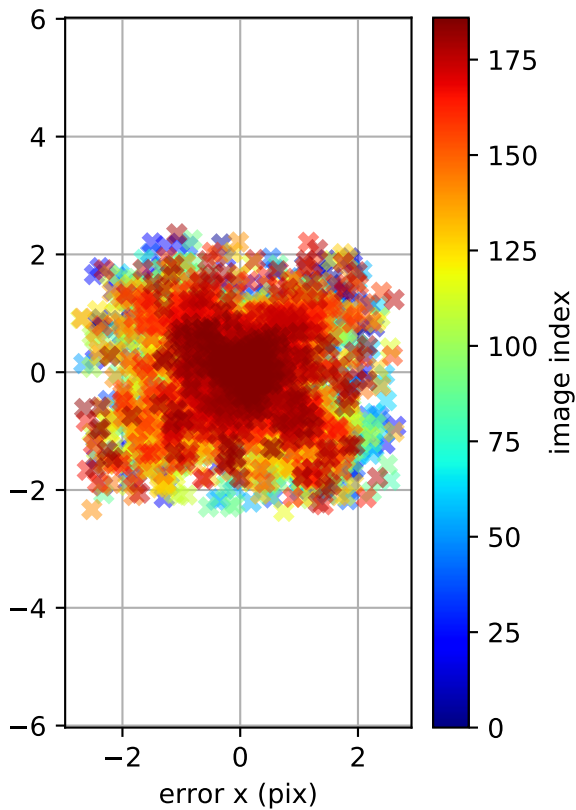
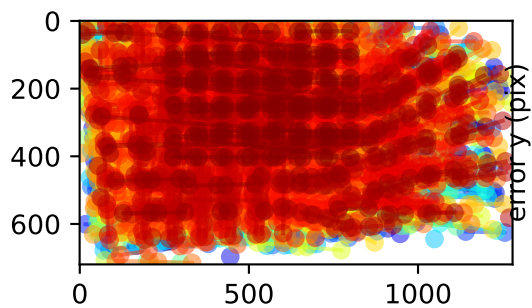
cam1: polar error



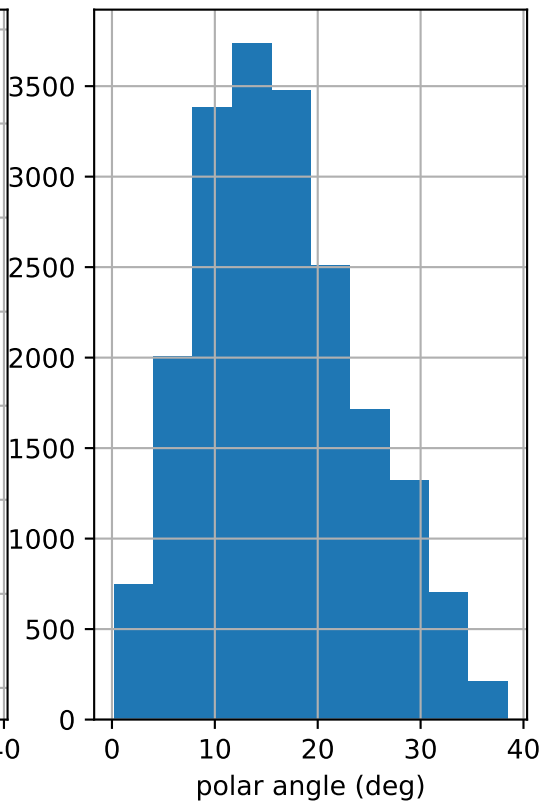
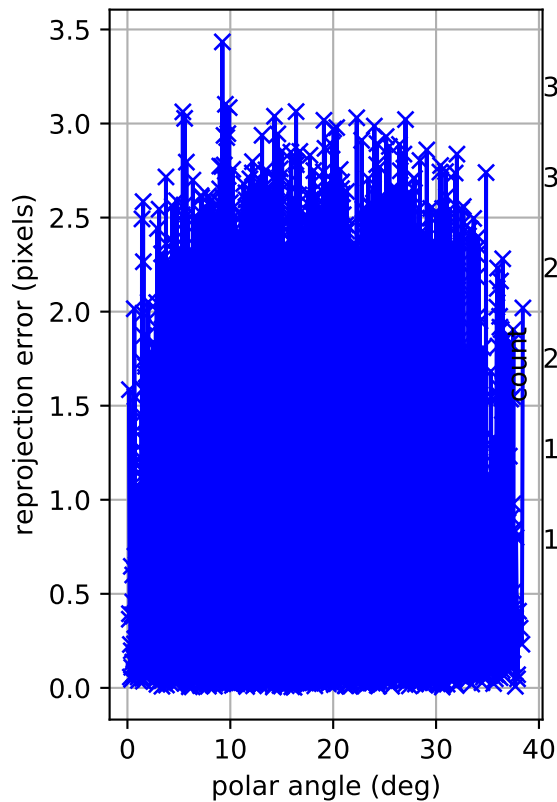
cam1: azimuthal error



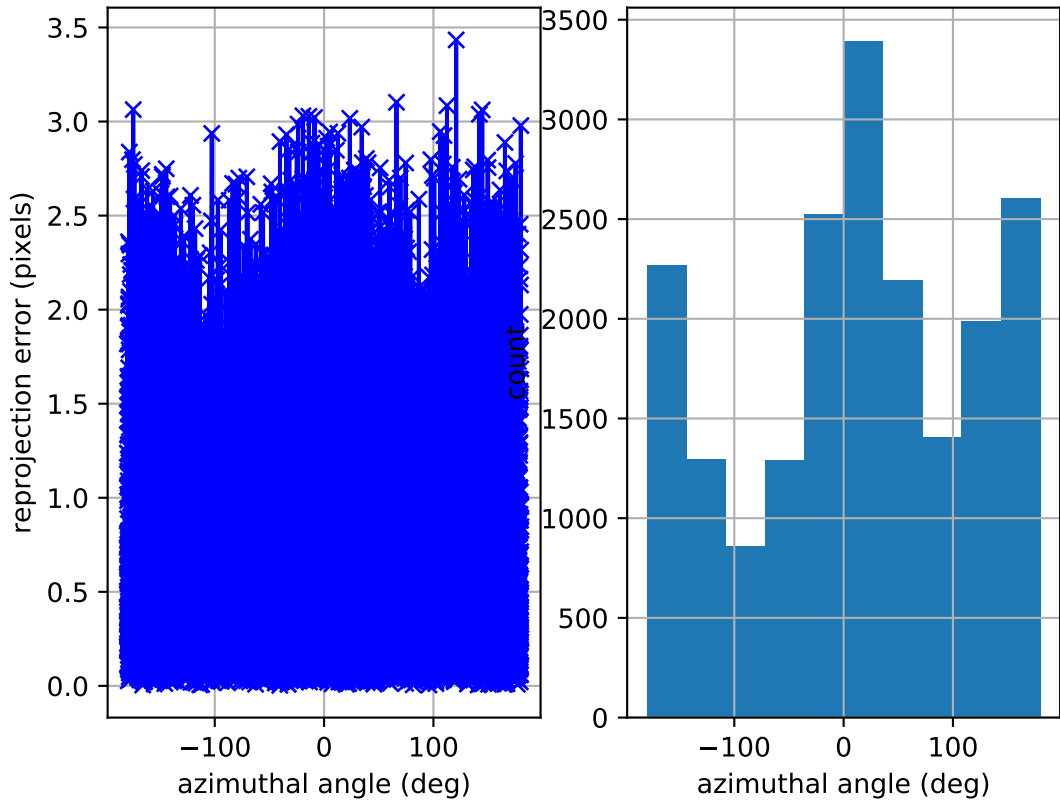
cam1: reprojection errors



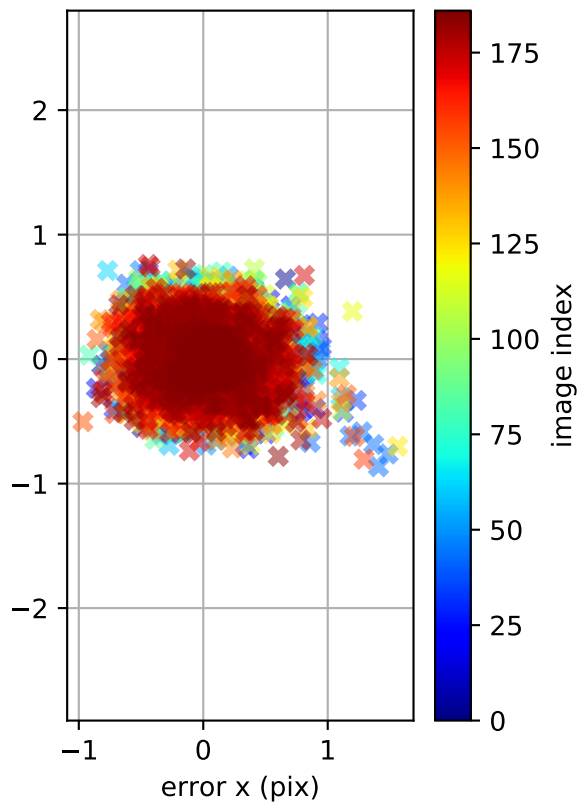
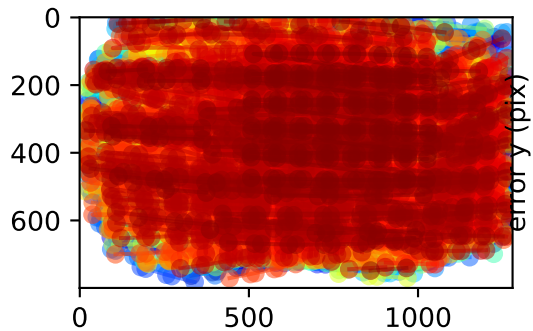
cam2: polar error



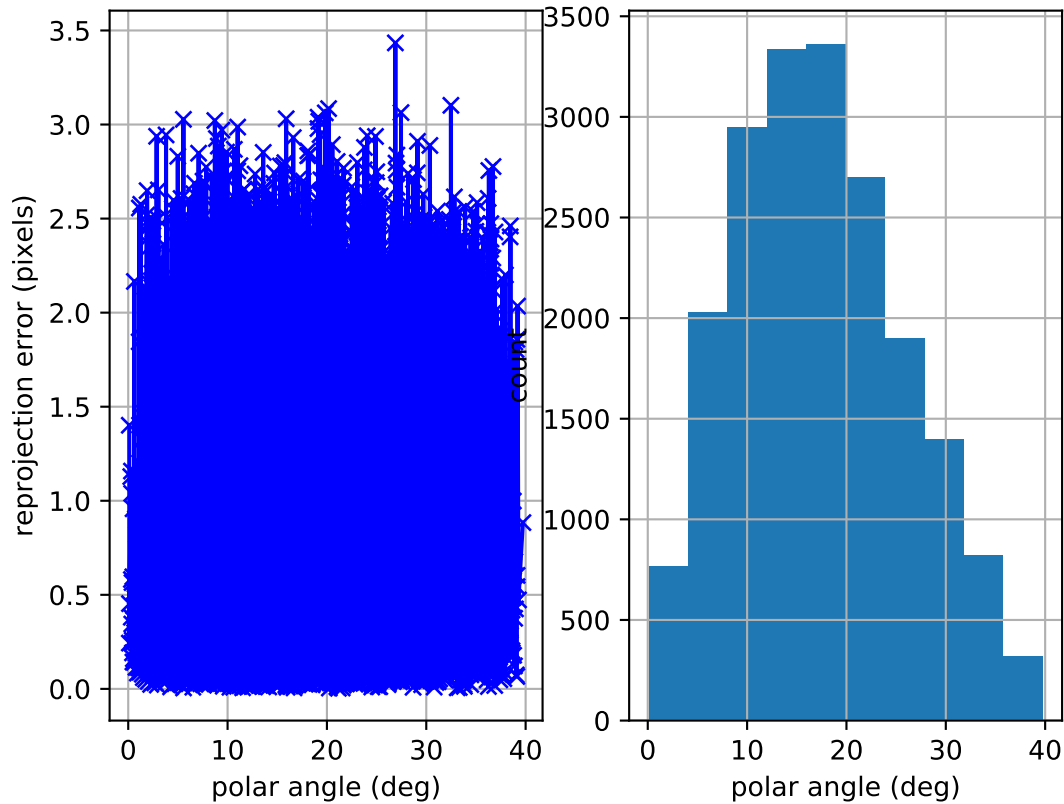
cam2: azimuthal error



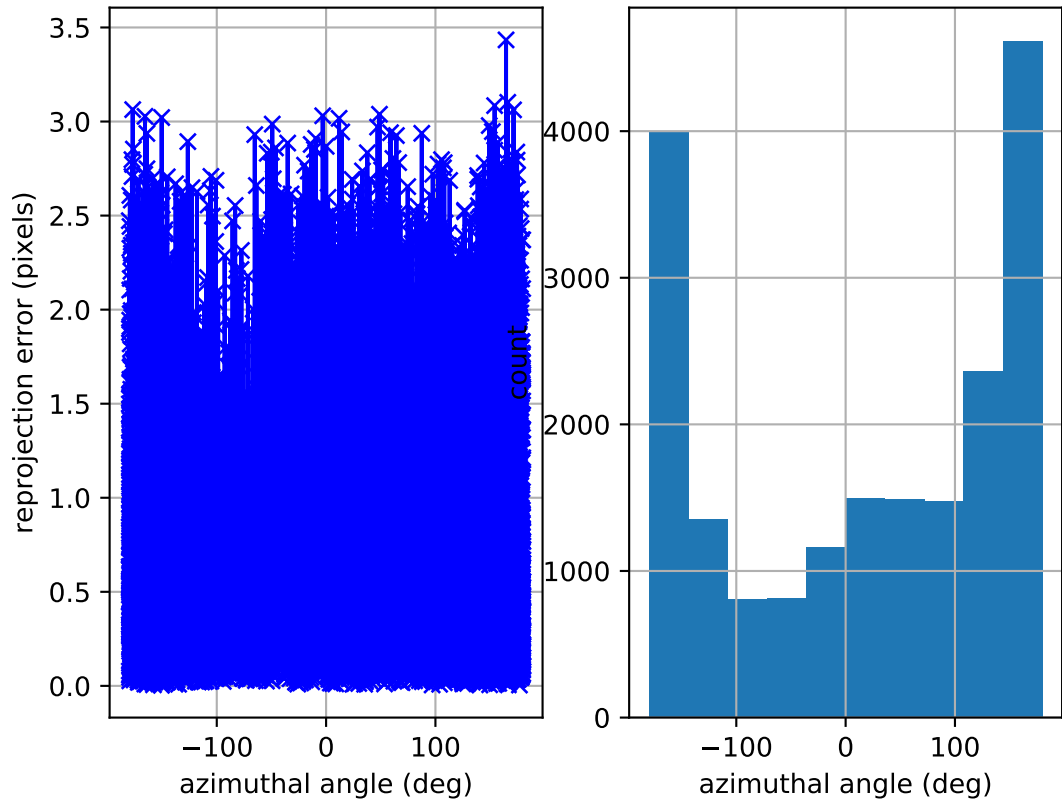
cam2: reprojection errors



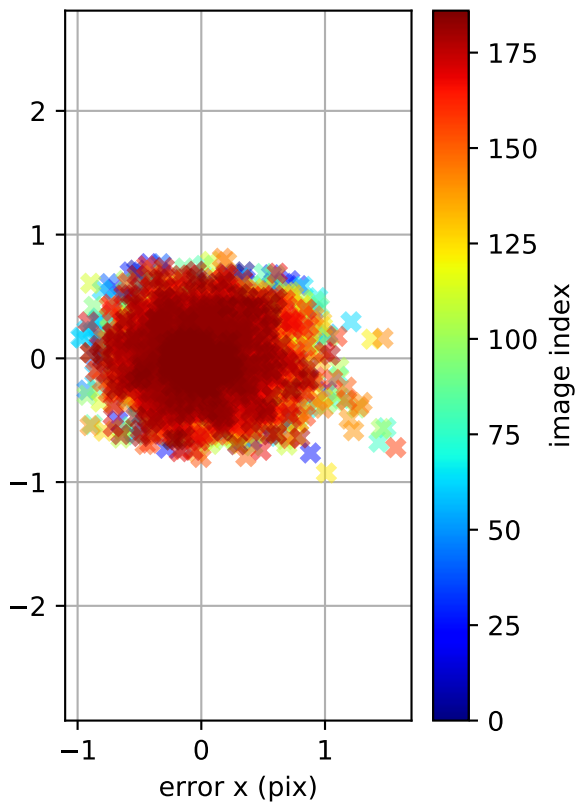
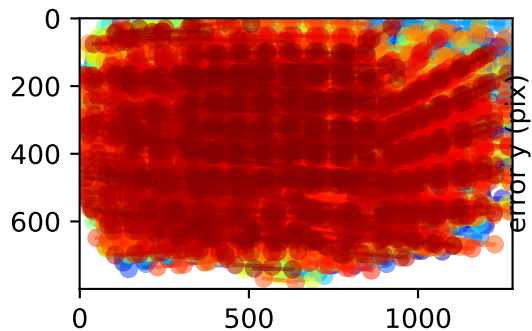
cam3: polar error



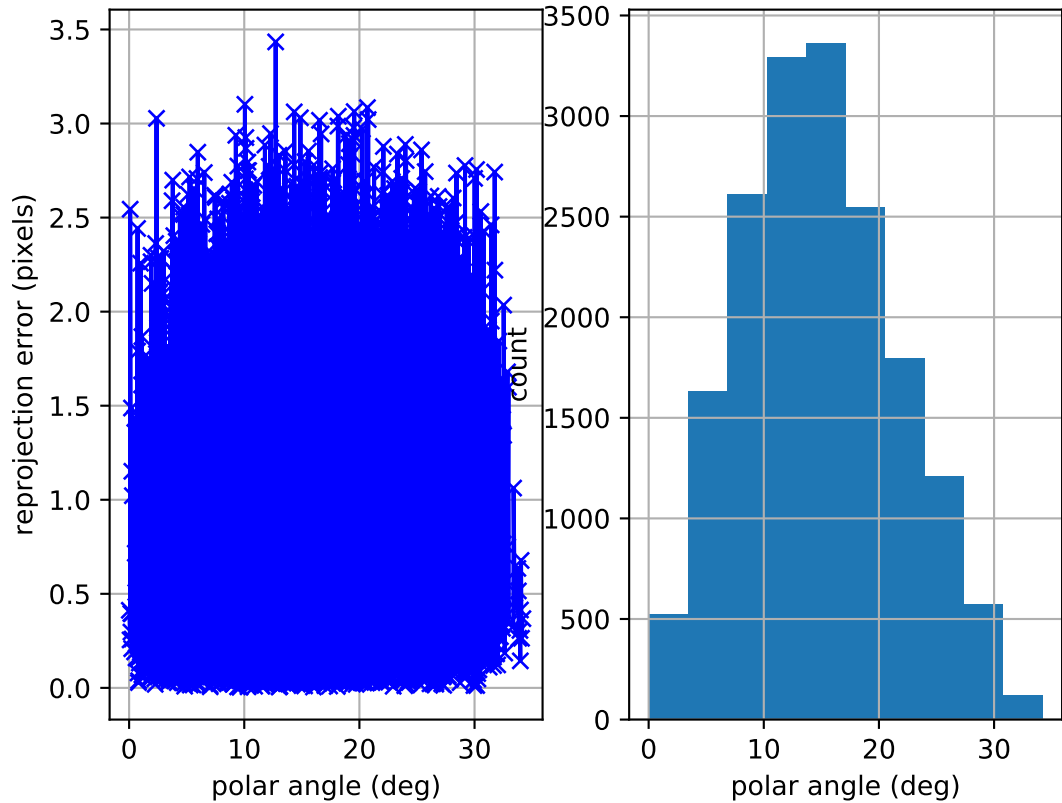
cam3: azimuthal error



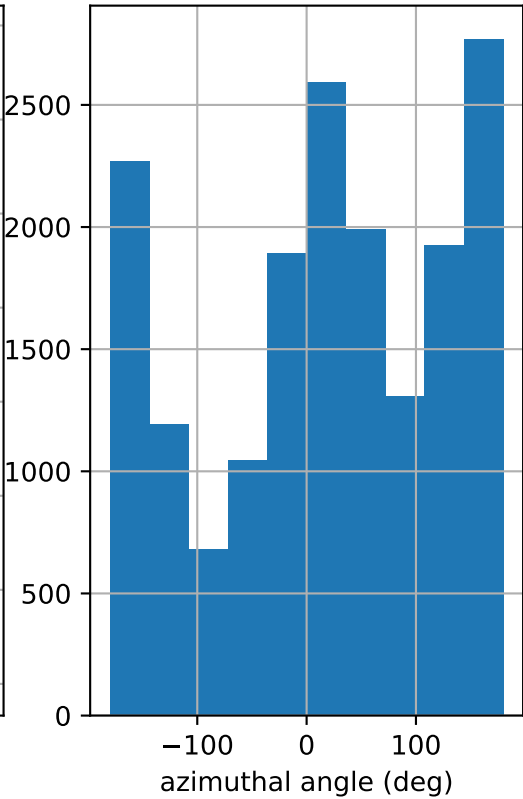
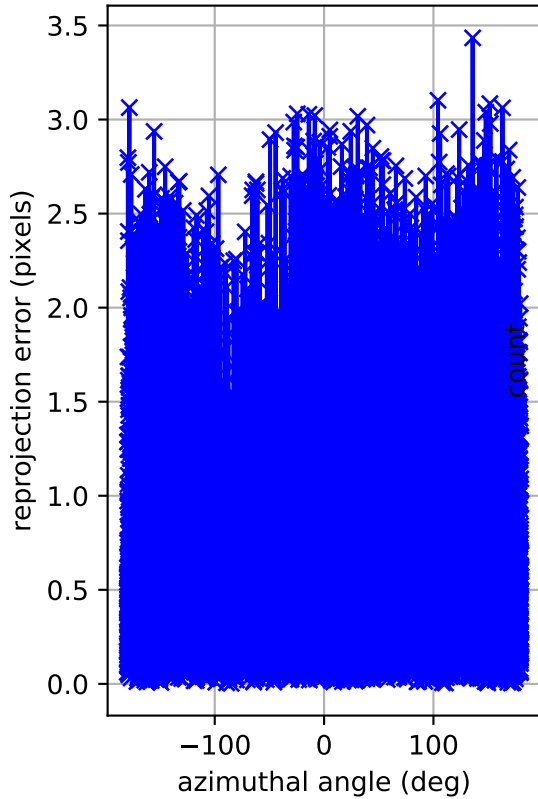
cam3: reprojection errors



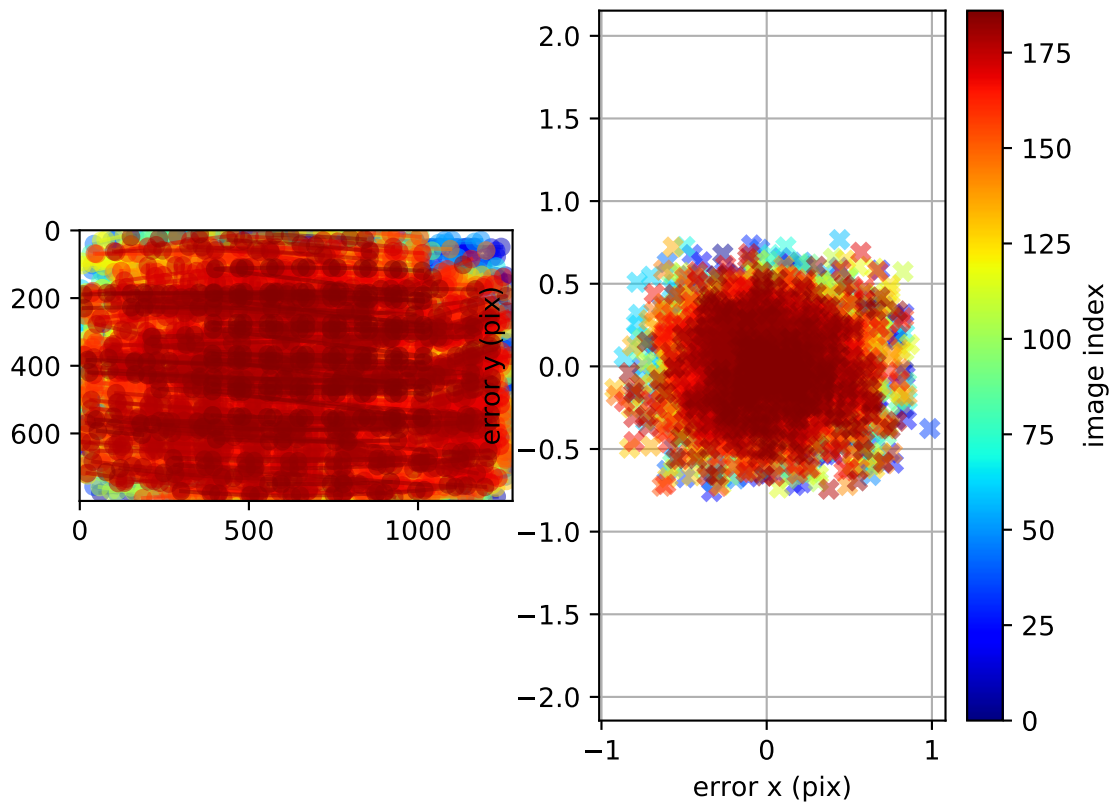
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

