

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.05104443 0.08420887 0.00010006 -0.00092964] +- [0.00106695 0.00232847 0.00009077 0.00006875]
projection: [1030.19462421 1029.3068588 633.83961879 362.23800177] +- [0.14260139 0.16263904 0.00631342 0.09200885]

reprojection error: [0.000049, -0.000229] +- [0.577158, 0.490324]

cam1 (/prophesee/right/events):

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

distortion: [-0.05840765 0.09040965 0.00122779 0.00005113] +- [0.00107807 0.00247792 0.00008948 0.00005638]
projection: [1029.81809755 1029.27092856 636.65819102 365.19484752] +- [0.15074521 0.16151786 0.00762595 0.08696364]

reprojection error: [0.000095, -0.000218] +- [0.580231, 0.503515]

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

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

distortion: [-0.39711598 0.1636178 0.00002696 0.00049278] +- [0.00058454 0.00106118 0.00006107 0.0000456]
projection: [1057.51877481 1057.24485906 675.00783685 336.23426332] +- [0.13986129 0.15005134 0.03387056 0.19035362]

reprojection error: [0.000217, -0.000183] +- [0.207498, 0.184305]

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

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

distortion: [-0.39609844 0.15758647 -0.00006988 0.00095242] +- [0.00050528 0.00089102 0.00006208 0.00003729]
projection: [1052.60593367 1052.49147206 672.90223778 328.22290367] +- [0.14613599 0.14836472 0.02297215 0.20739798]

reprojection error: [0.000258, -0.000051] +- [0.204242, 0.174841]

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

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

distortion: [-0.41669413 0.18831148 0.0002131 -0.00018571] +- [0.00084337 0.0022059 0.0000626 0.00004506]
projection: [1263.53179473 1262.74540022 654.92489227 366.96647192] +- [0.14222411 0.1479434 0.00485849 0.06037752]

reprojection error: [0.000059, 0.000143] +- [0.257731, 0.231908]

baseline T_1_0:

q: [-0.00018903 0.00235657 -0.00028519 0.99999716] +- [0.00012741 0.00004928 0.00004668]

t: [-0.12011256 0.00089973 -0.00023867] +- [0.00003294 0.00003595 0.00013069]

baseline T_2_1:

q: [-0.00034514 -0.00374107 -0.00452714 0.99998269] +- [0.00016756 0.00005877 0.00004347]

t: [0.12026653 0.06910046 0.00466845] +- [0.00003089 0.00003286 0.00012715]

baseline T_3_2:

q: [0.00021653 0.00061677 0.00026878 0.99999975] +- [0.00036146 0.0000652 0.00003728]

t: [-0.11997011 -0.00011287 0.0005519] +- [0.00002953 0.0000307 0.00013469]

baseline T_4_3:

q: [0.00203947 0.00246715 0.00037357 0.99999481] +- [0.00020356 0.00004247 0.00003572]

t: [0.08876744 0.00618542 0.00298248] +- [0.00002735 0.00002765 0.00011819]

Target configuration

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Type: aprilgrid

Tags:

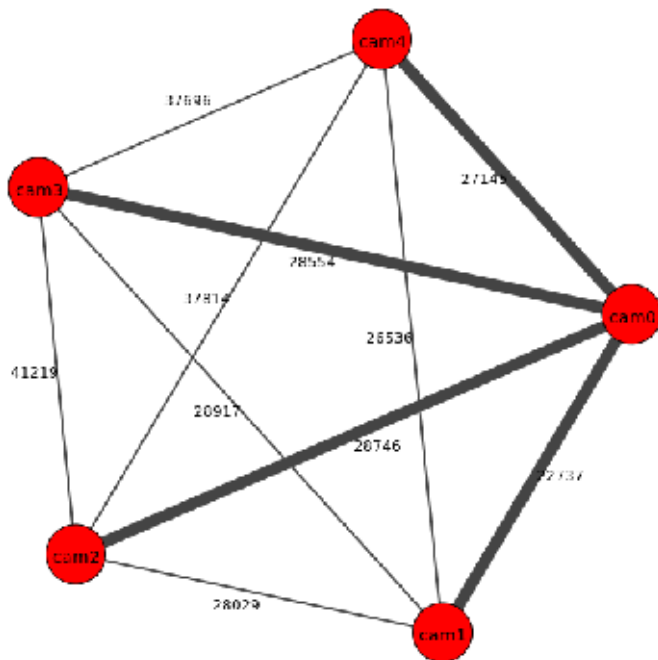
Rows: 5

Cols: 7

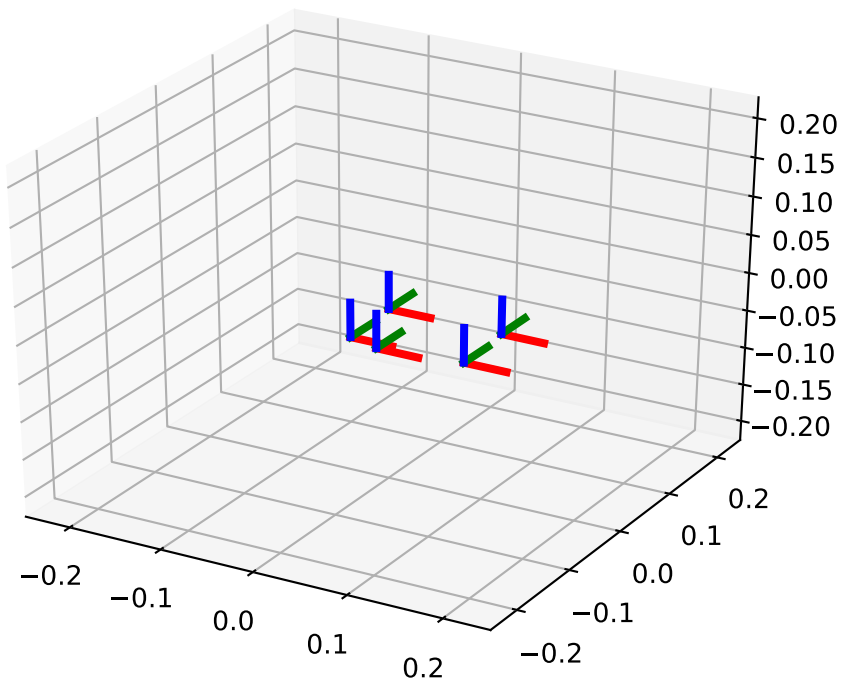
Size: 0.04 [m]

Spacing 0.01 [m]

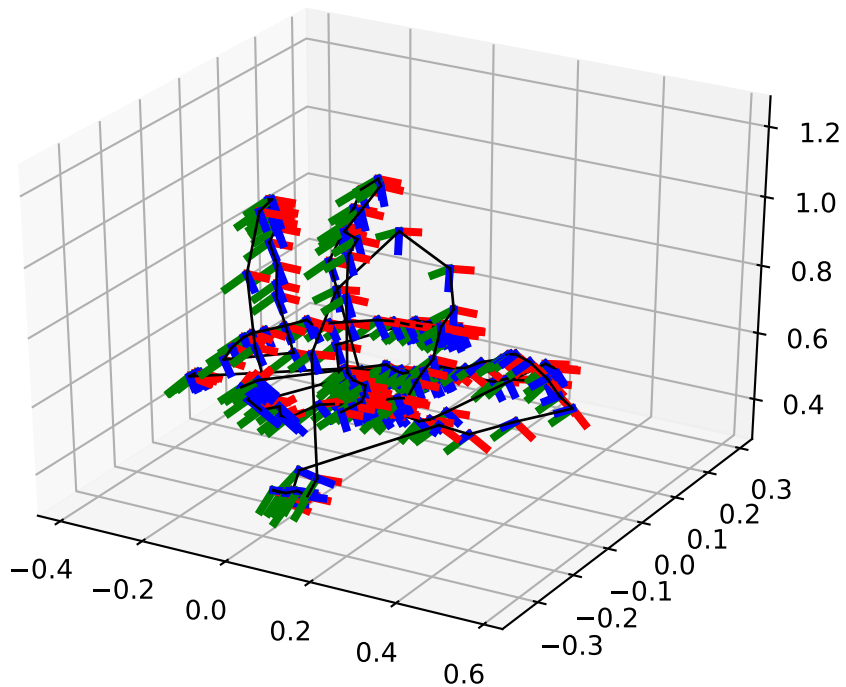
Inter-camera observations graph (edge weight=#mutual obs.)



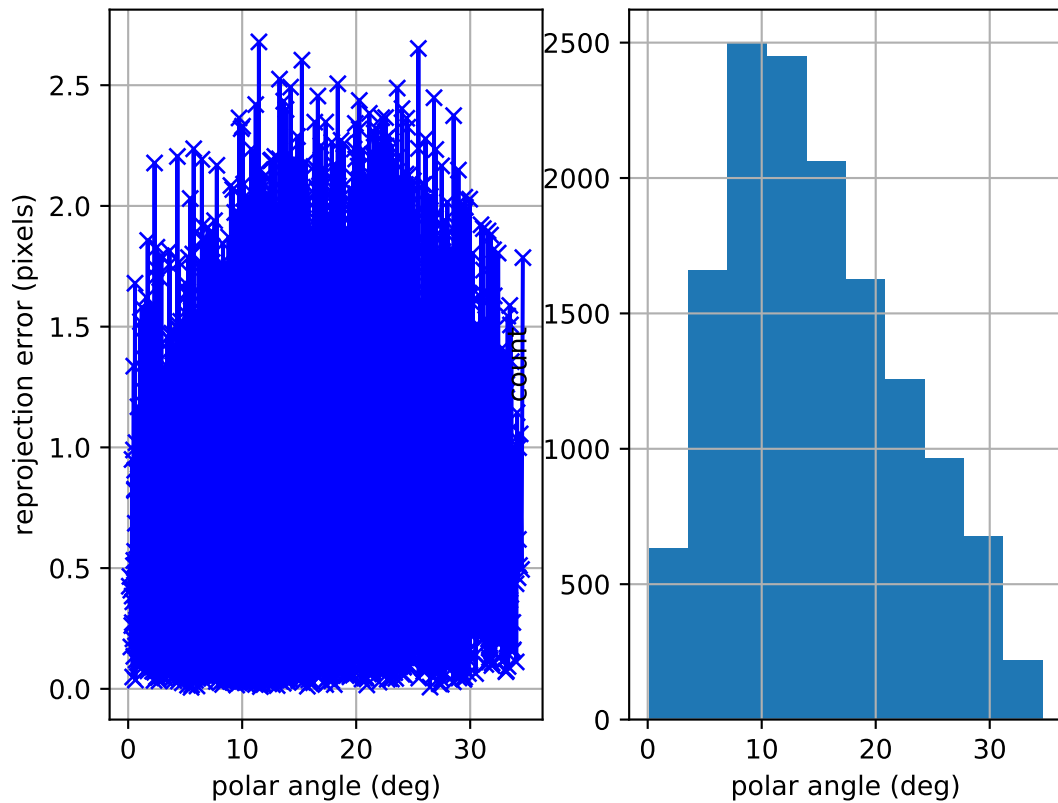
camera system



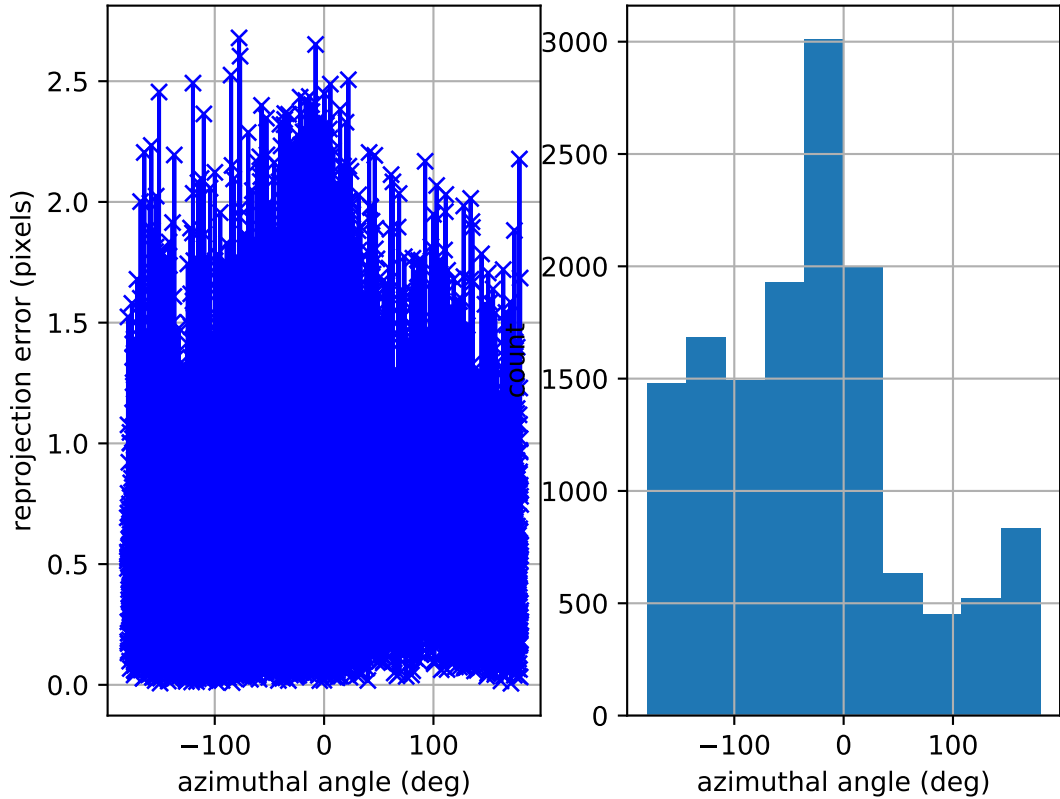
cam0: estimated poses



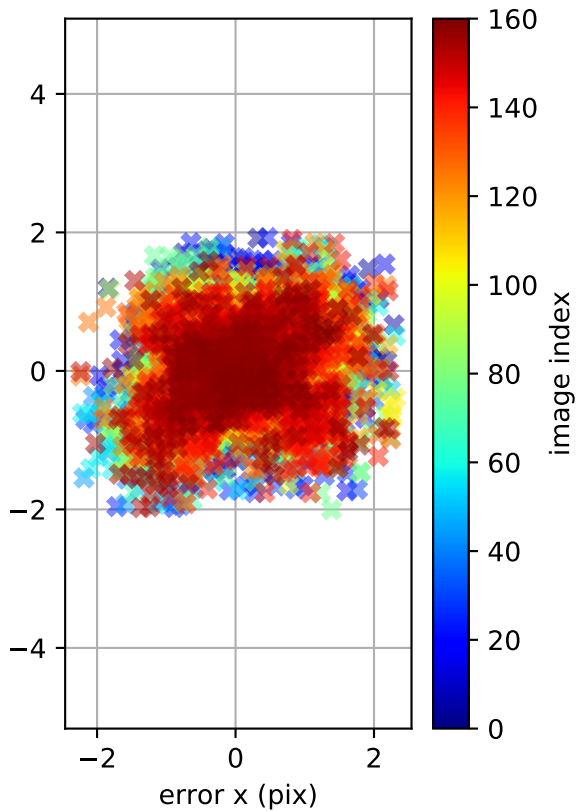
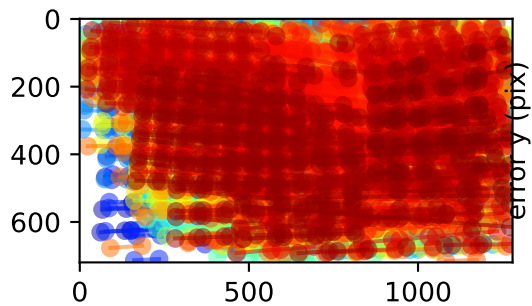
cam0: polar error



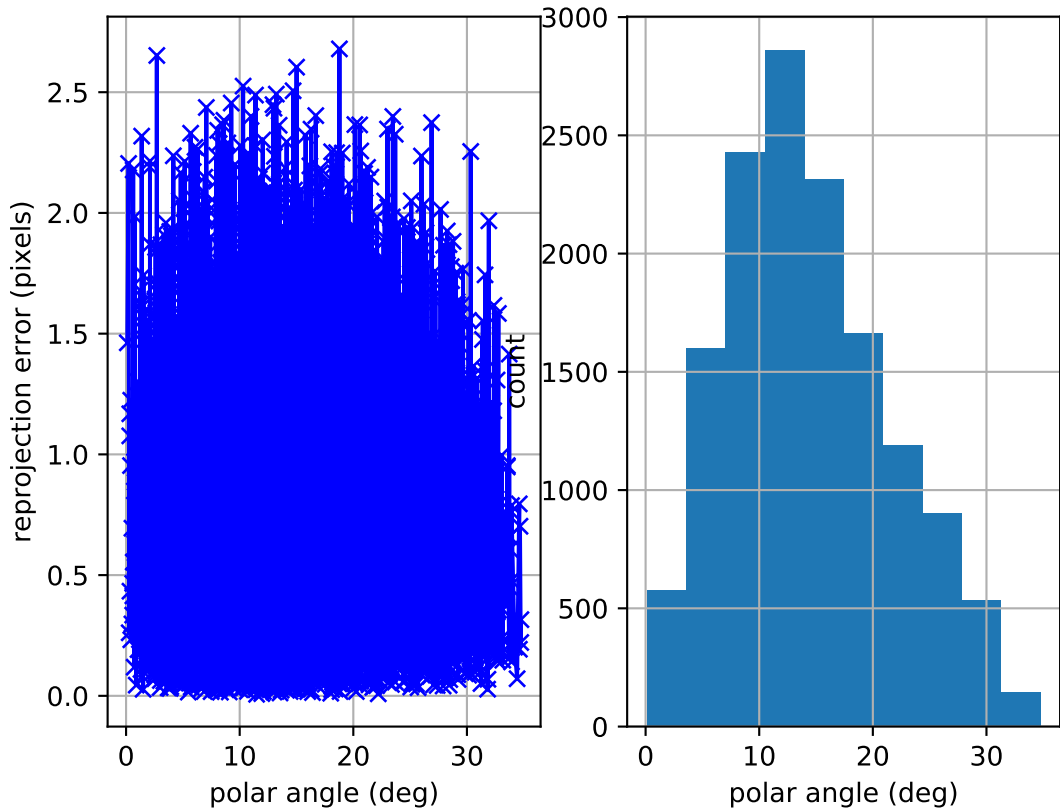
cam0: azimuthal error



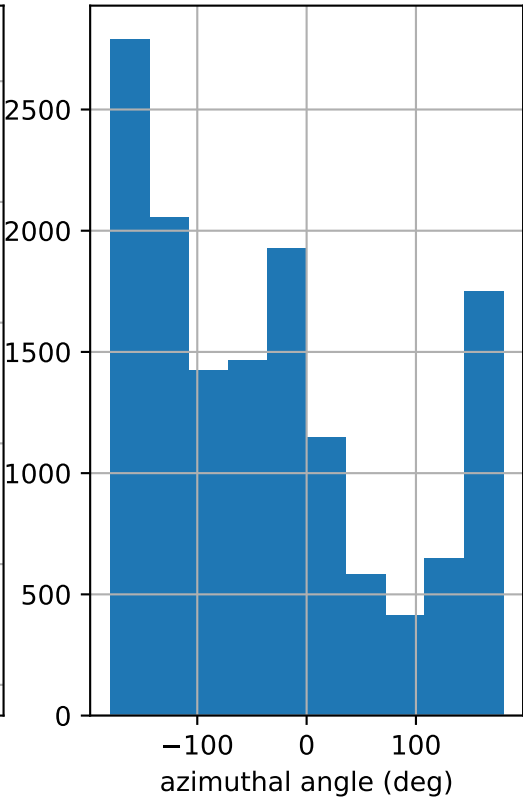
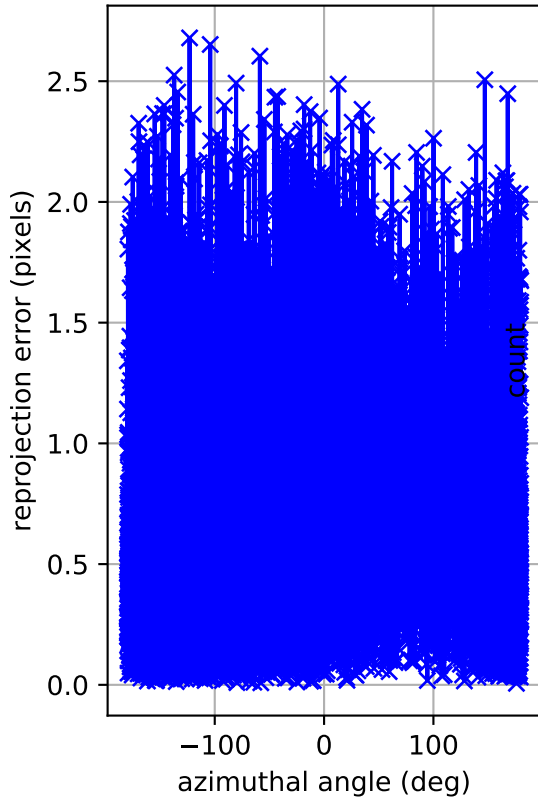
cam0: reprojection errors



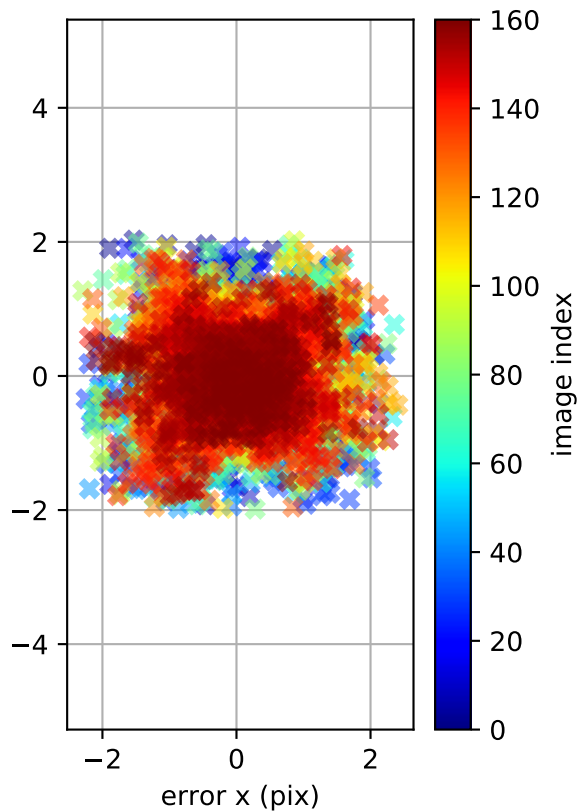
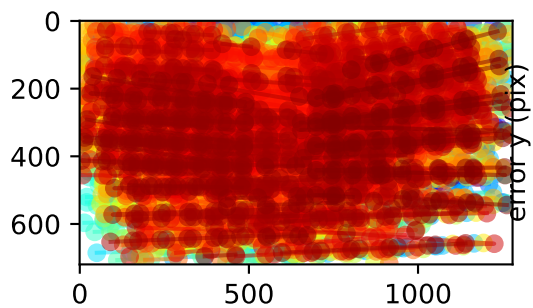
cam1: polar error



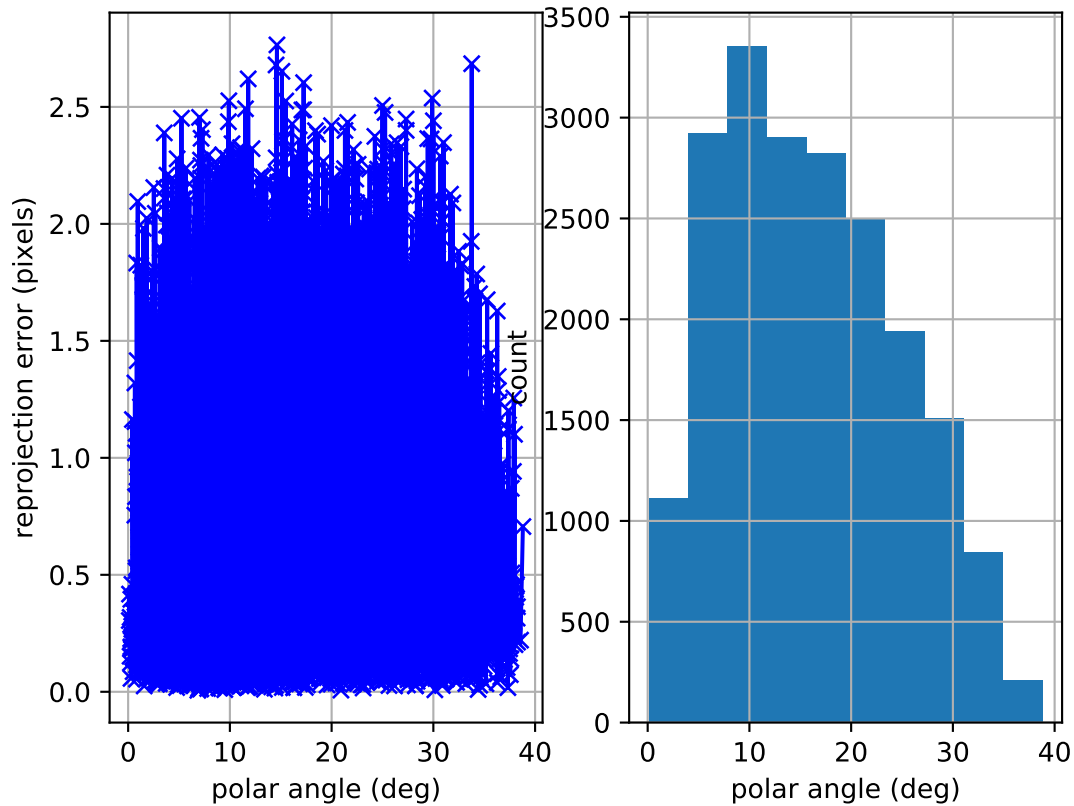
cam1: azimuthal error



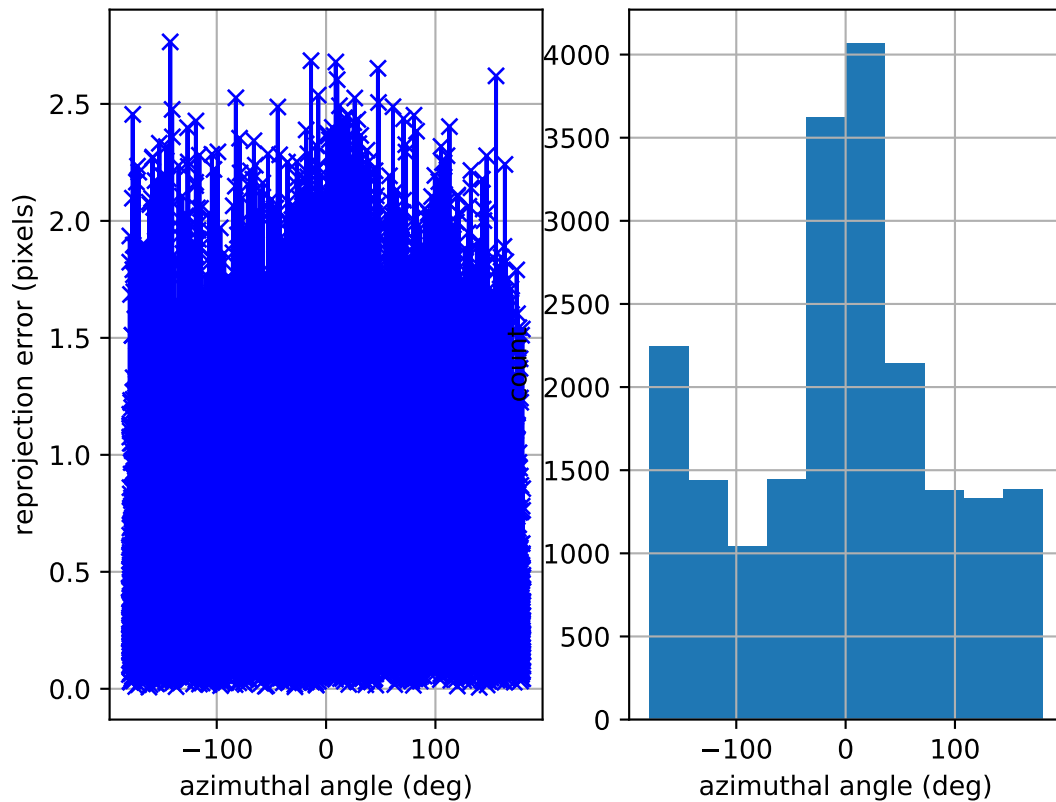
cam1: reprojection errors



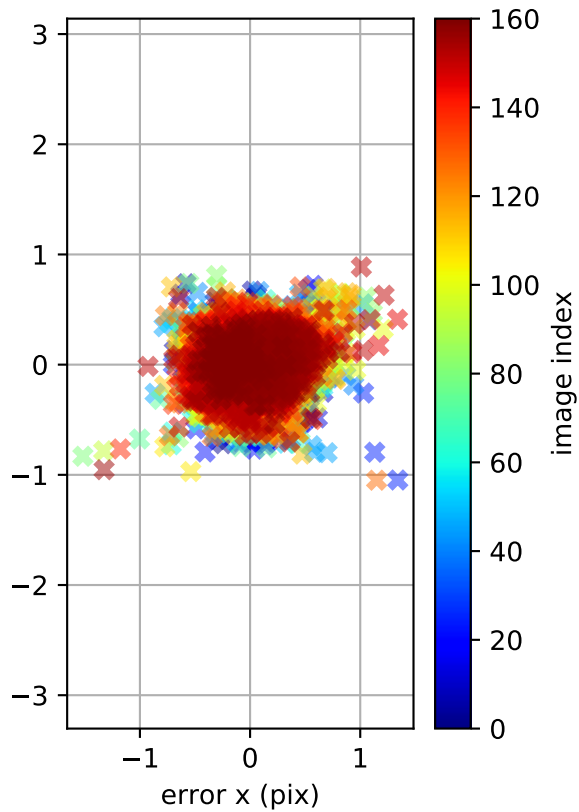
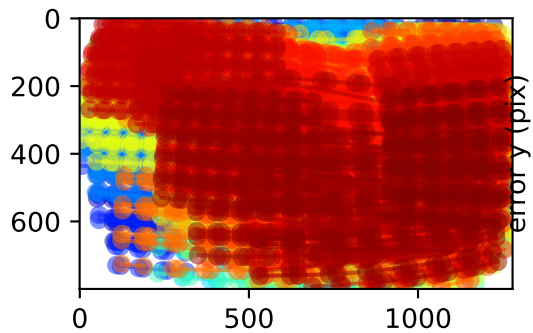
cam2: polar error



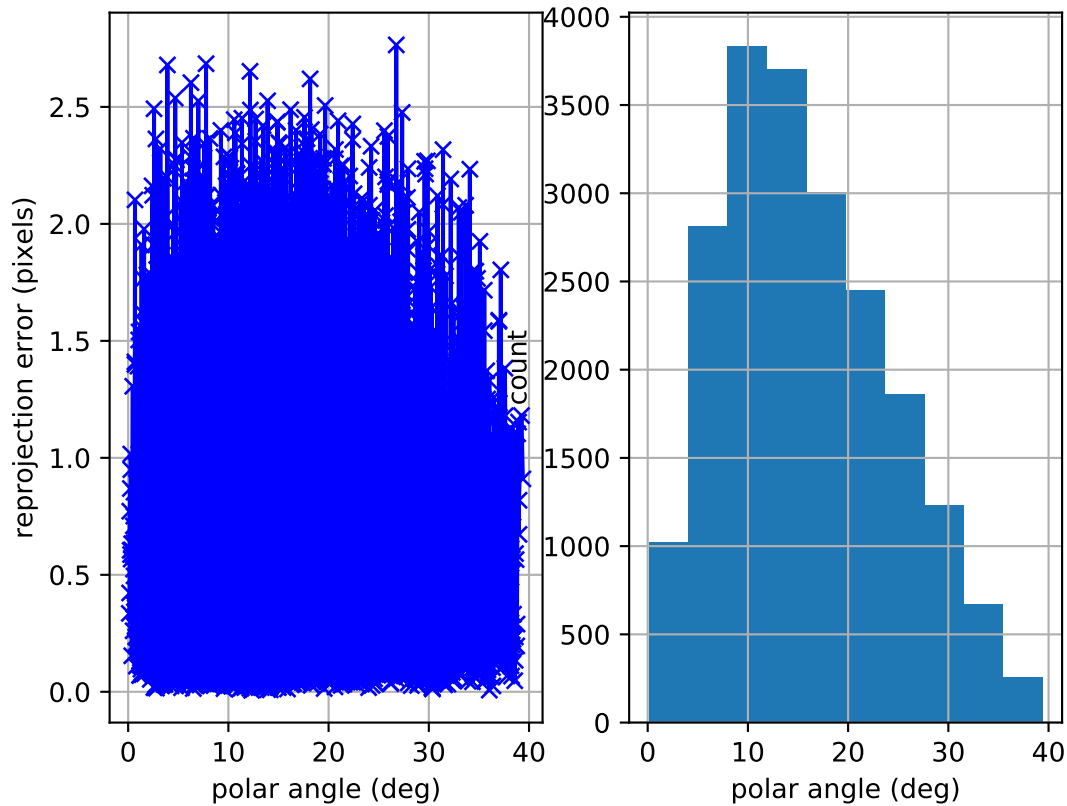
cam2: azimuthal error



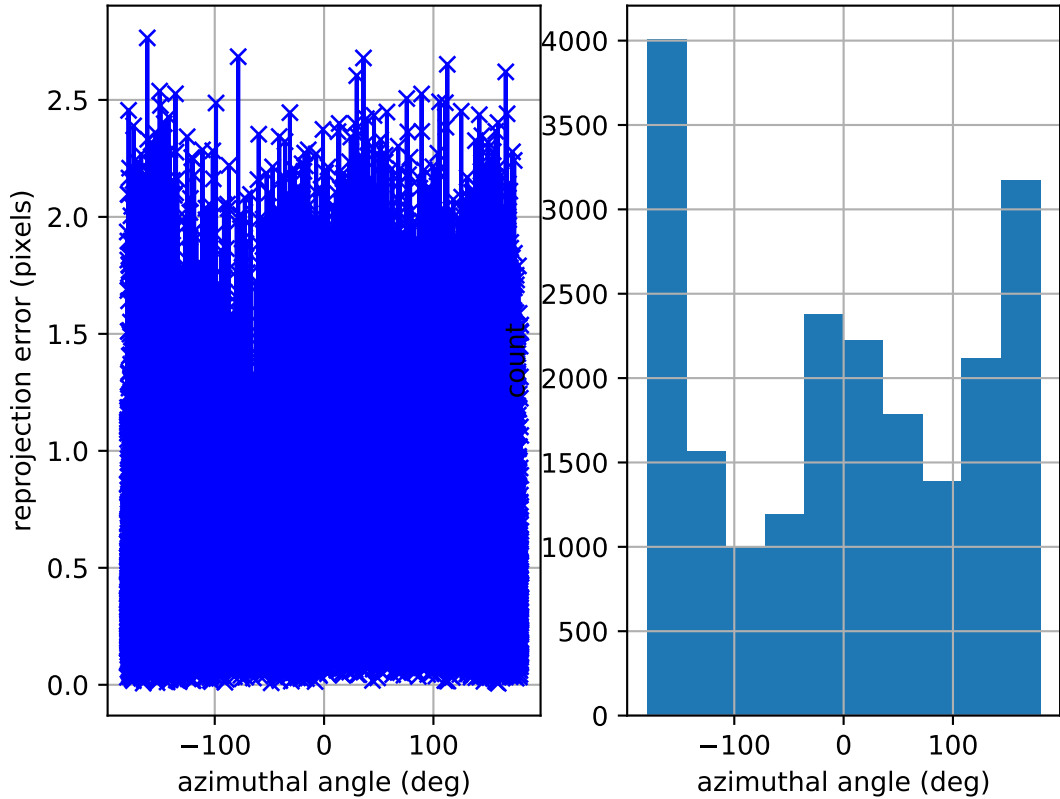
cam2: reprojection errors



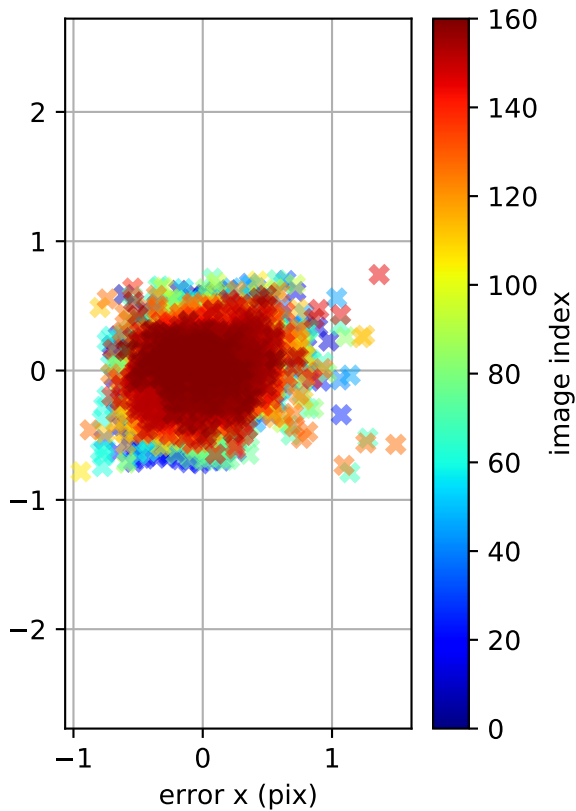
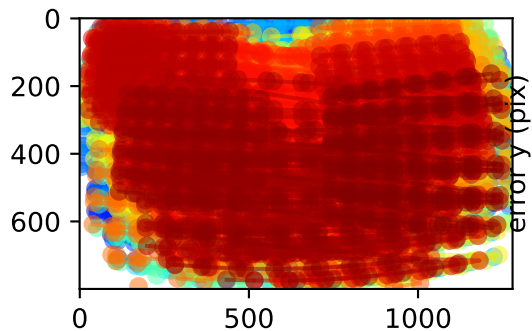
cam3: polar error



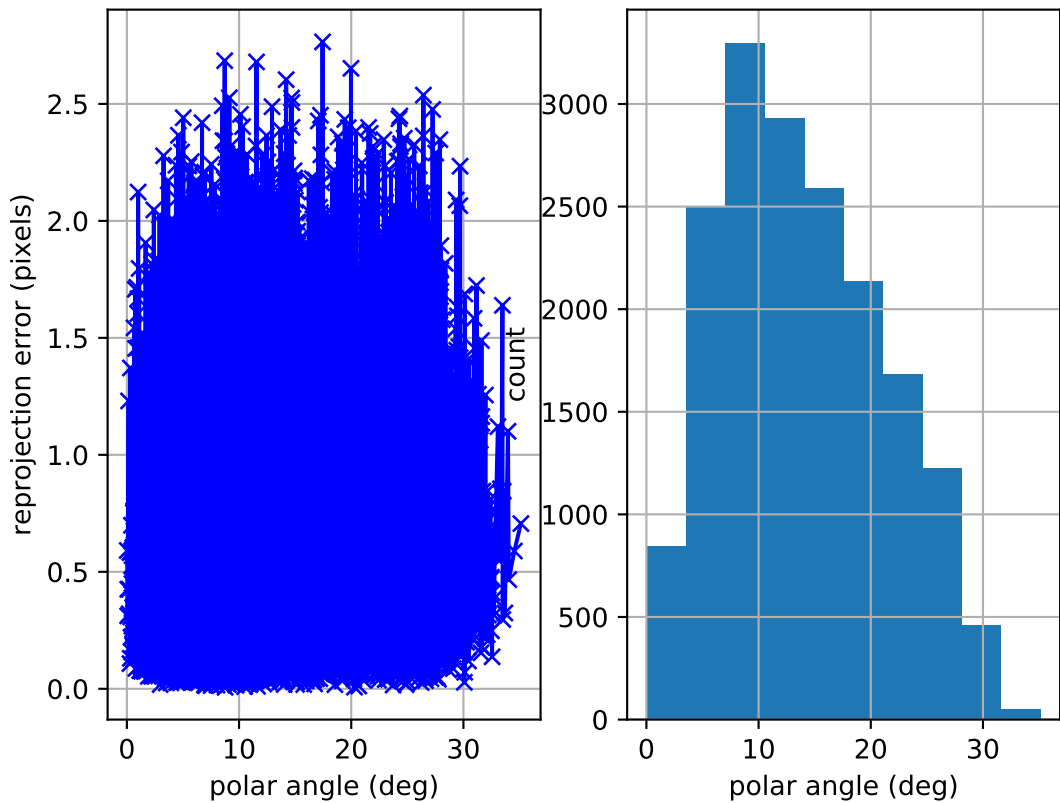
cam3: azimuthal error



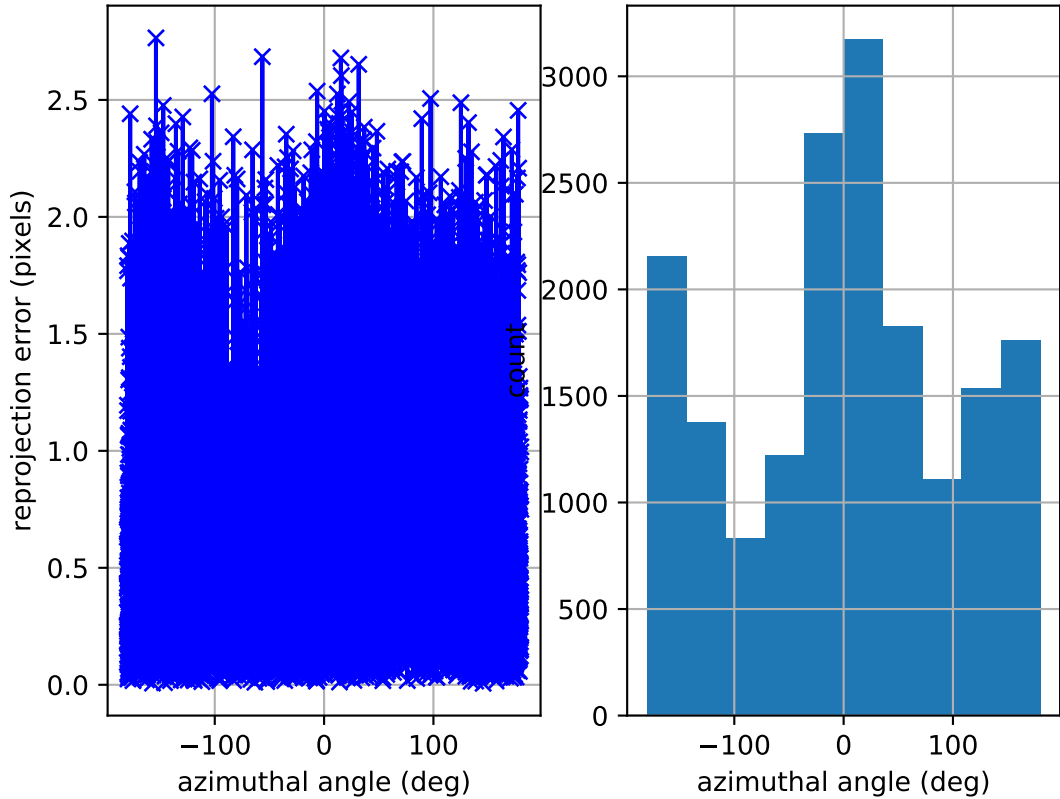
cam3: reprojection errors



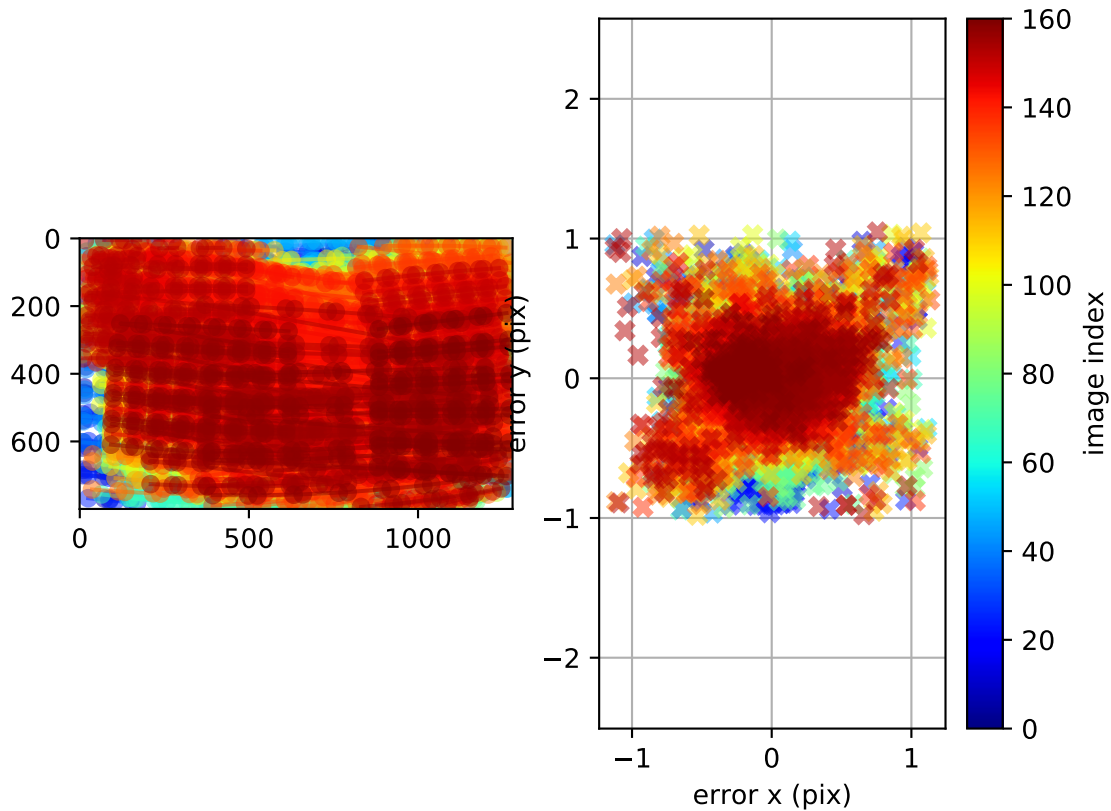
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

