

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.0484265 0.08073155 0.00012441 -0.00083685] +- [0.00106665 0.00246152 0.00008045 0.00005325]

projection: [1031.59485848 1030.65501832 634.60350367 362.1832057] +- [0.15041539 0.15530471 0.00590531 0.10384579]

reprojection error: [0.000112, -0.000095] +- [0.610906, 0.510559]

cam1 (/prophesee/right/events):

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

distortion: [-0.05458654 0.08011707 0.00115205 0.00010648] +- [0.00112188 0.00261003 0.00008234 0.00005353]

projection: [1030.39580992 1029.69619031 637.13188264 364.83160562] +- [0.15916336 0.1610227 0.00223828 0.08411272]

reprojection error: [0.000135, -0.000109] +- [0.673635, 0.581705]

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

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

distortion: [-0.39721471 0.16336186 0.00016952 0.00046632] +- [0.00053887 0.00099244 0.0000599 0.00003437]

projection: [1057.5417674 1057.13680365 674.42780691 334.66960944] +- [0.1322816 0.13698952 0.0027233 0.24555203]

reprojection error: [0.000154, -0.000130] +- [0.205933, 0.167500]

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

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

distortion: [-0.39437134 0.15462115 0.00002971 0.00088419] +- [0.00045163 0.00073032 0.00005569 0.00003388]

projection: [1052.36335834 1052.57415166 672.29630464 327.66139809] +- [0.13570026 0.13780688 0.00428071 0.24546014]

reprojection error: [0.000164, -0.000180] +- [0.229661, 0.170394]

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

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

distortion: [-0.41917821 0.19579933 0.00024844 -0.00019186] +- [0.0008043 0.00213665 0.00005626 0.00003571]

projection: [1263.34780031 1262.63013381 653.17082101 366.0328344] +- [0.1326697 0.1362356 0.00235074 0.12469776]

reprojection error: [0.000043, -0.000119] +- [0.212230, 0.181758]

baseline T_1_0:

q: [-0.00006611 0.00211581 -0.00031454 0.99999771] +- [0.0000821 0.00004799 0.00004531]

t: [-0.12016093 0.00093088 -0.00073567] +- [0.0000282 0.00002741 0.00012462]

baseline T_2_1:

q: [0.00011046 -0.00411413 -0.00476369 0.99998018] +- [0.00026574 0.0000441 0.00004162]

t: [0.1202559 0.06929945 0.0040623] +- [0.00002592 0.000026 0.00011789]

baseline T_3_2:

q: [-0.0002727 0.00051767 0.00032298 0.99999978] +- [0.00034222 0.00003958 0.00003594]

t: [-0.11997099 -0.00012981 0.0008342] +- [0.00002364 0.00002382 0.00010615]

baseline T_4_3:

q: [0.00213377 0.00213316 0.00032322 0.9999954] +- [0.0002986 0.00003605 0.00003454]

t: [0.08882695 0.00624419 0.00254076] +- [0.0000218 0.00002201 0.00010015]

Target configuration

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Type: aprilgrid

Tags:

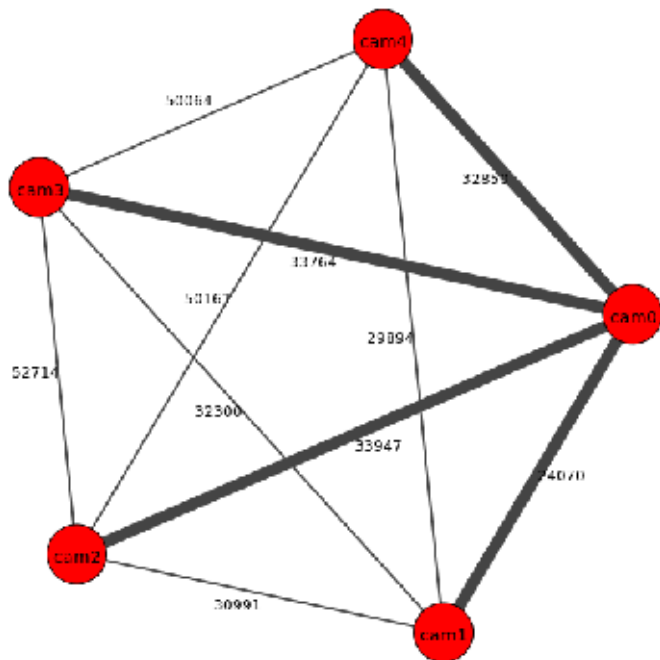
Rows: 5

Cols: 7

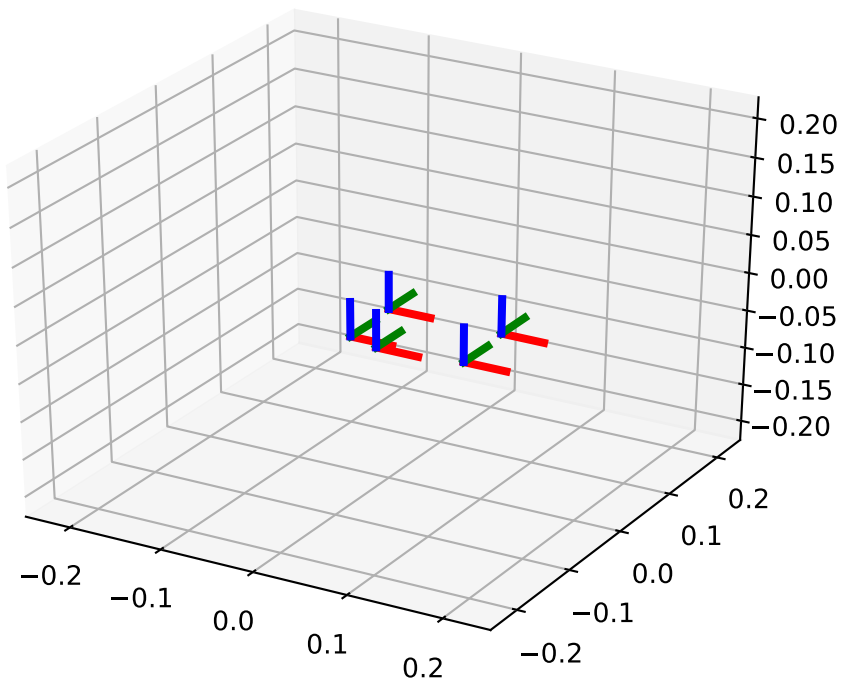
Size: 0.04 [m]

Spacing 0.01 [m]

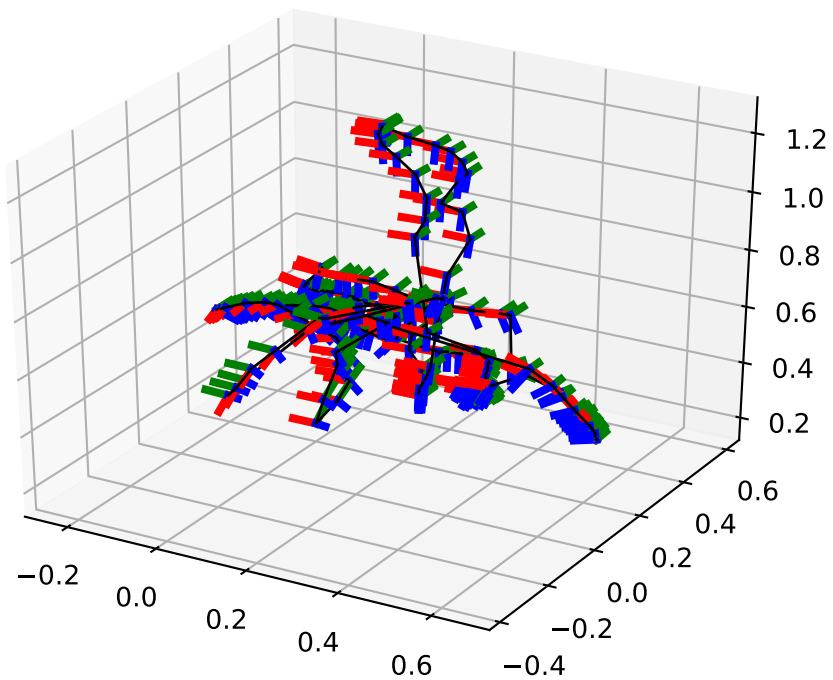
Inter-camera observations graph (edge weight=#mutual obs.)



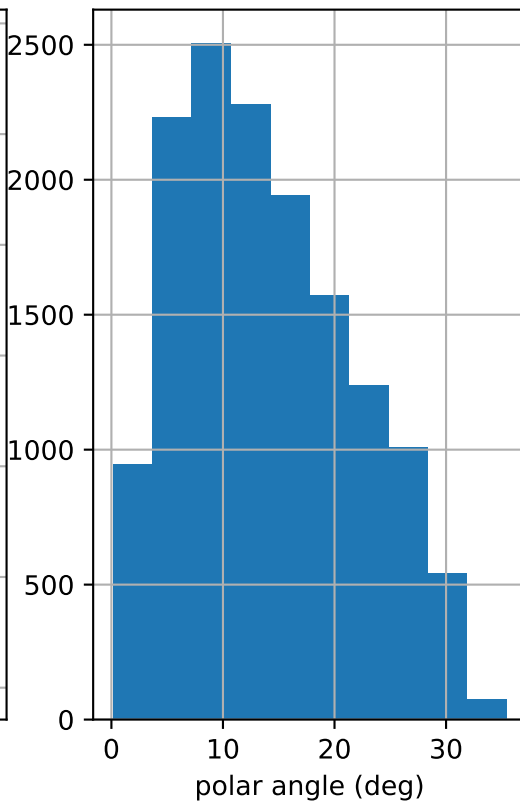
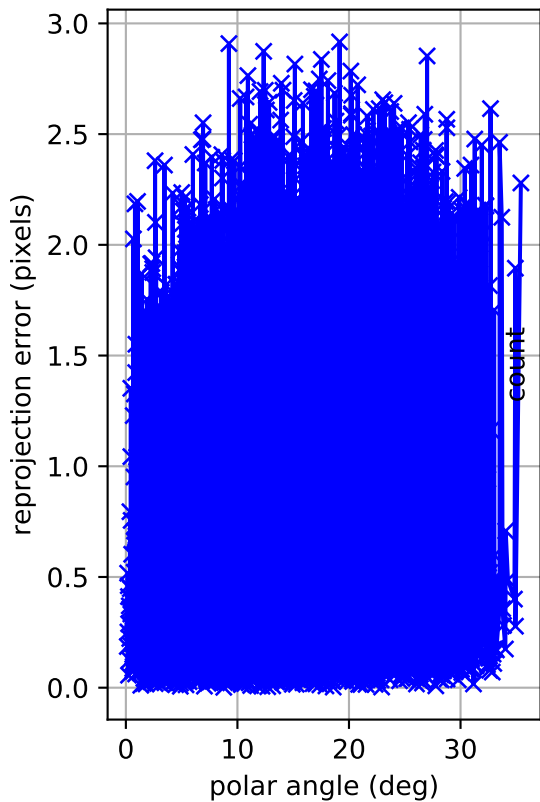
camera system



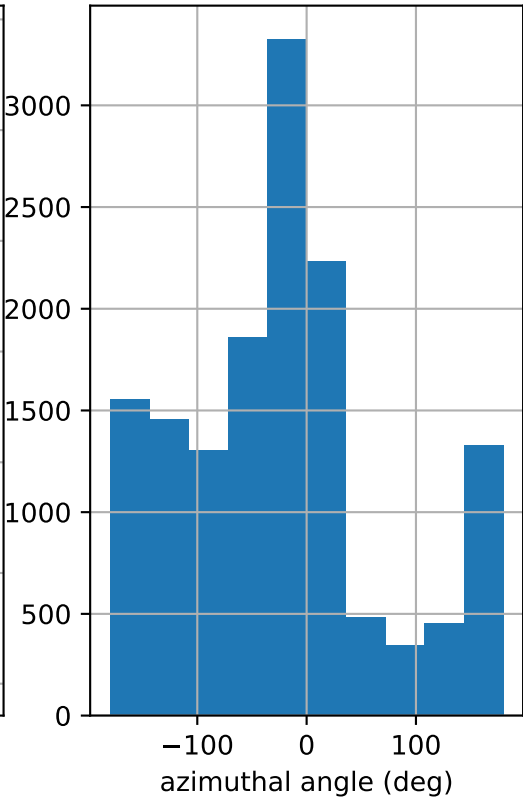
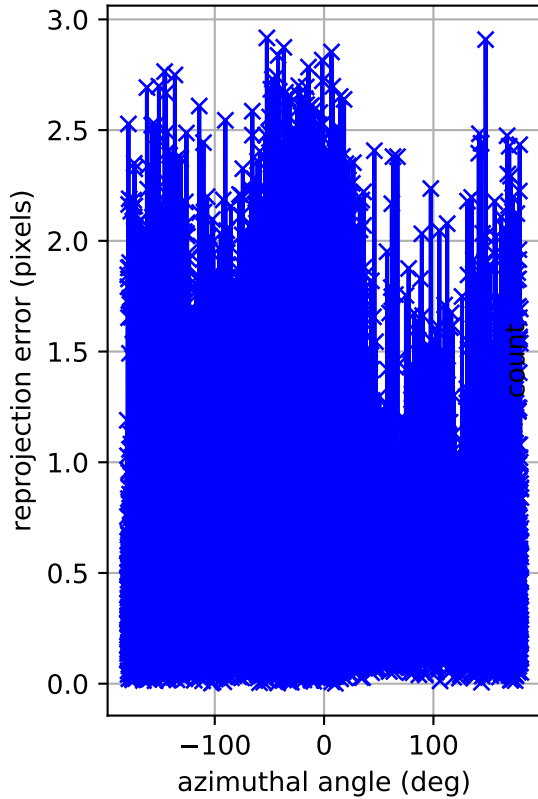
cam0: estimated poses



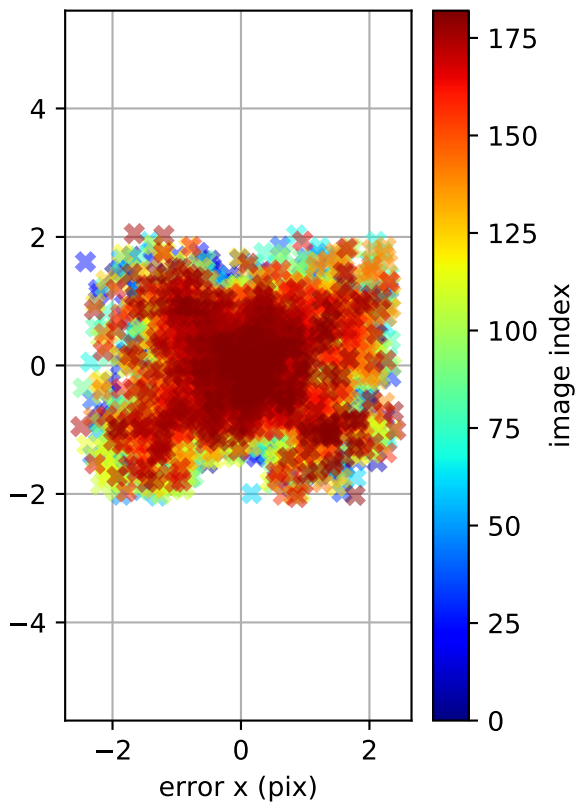
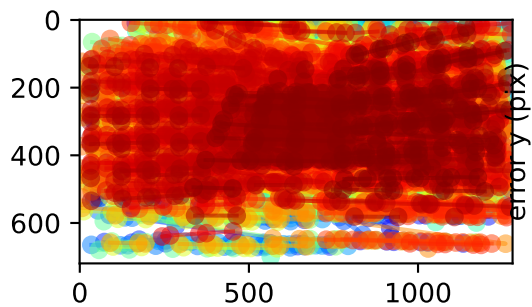
cam0: polar error



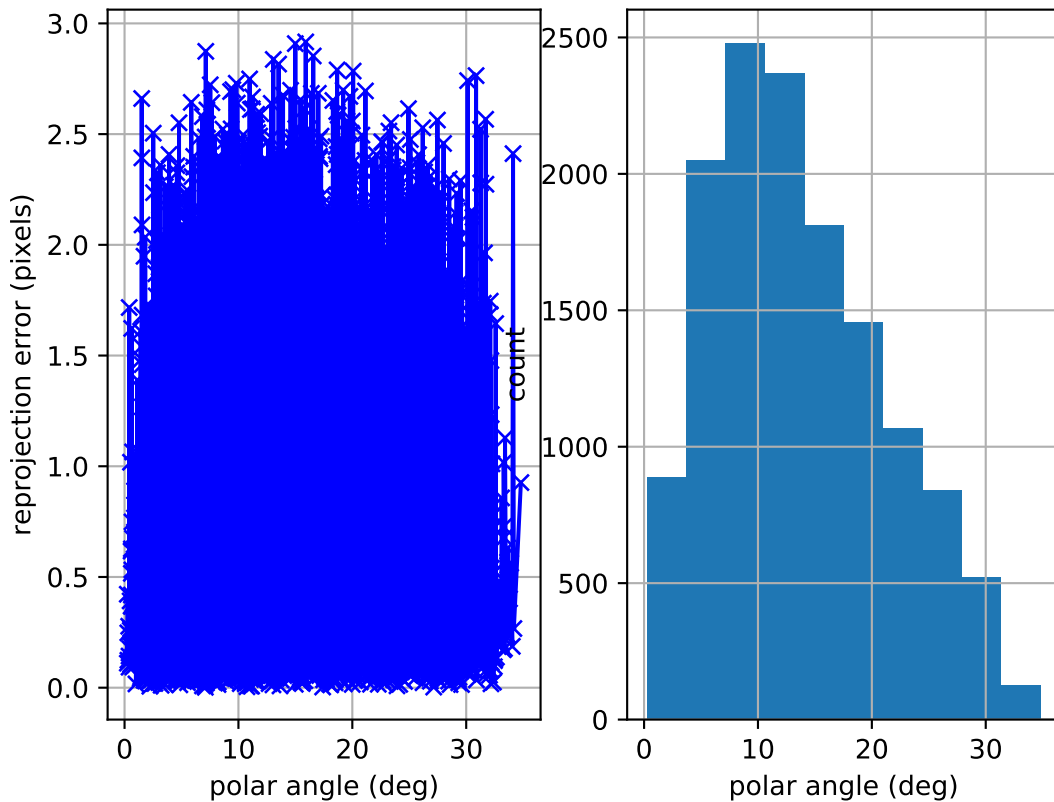
cam0: azimuthal error



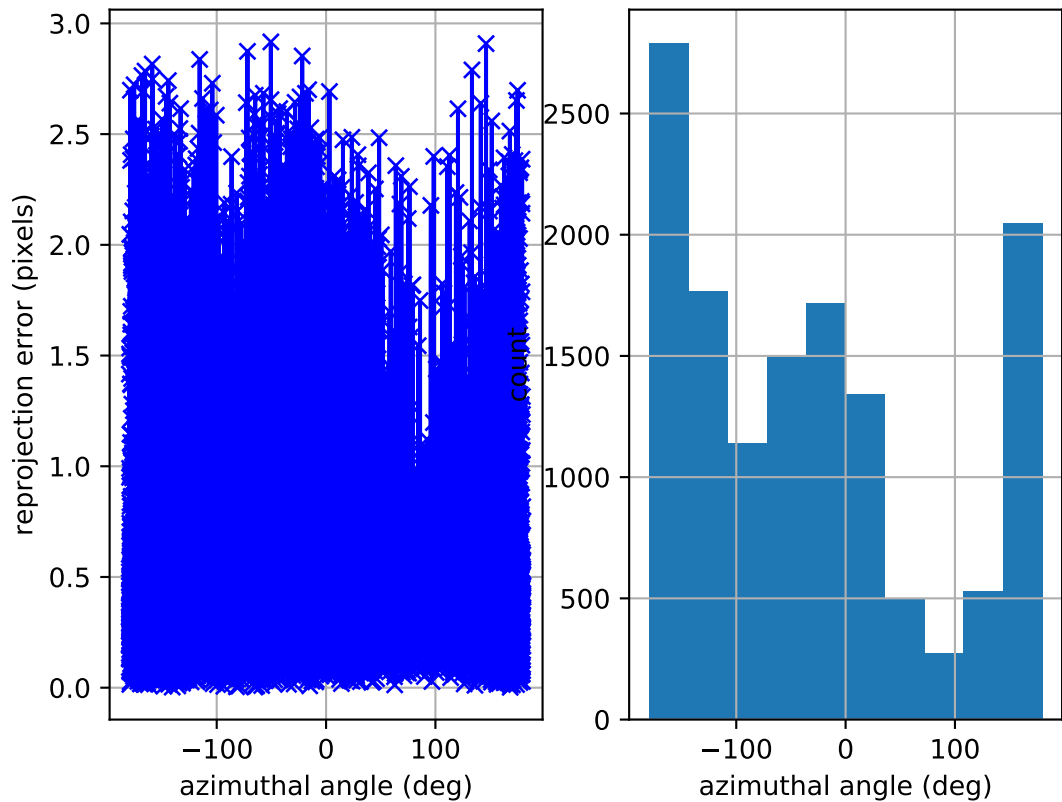
cam0: reprojection errors



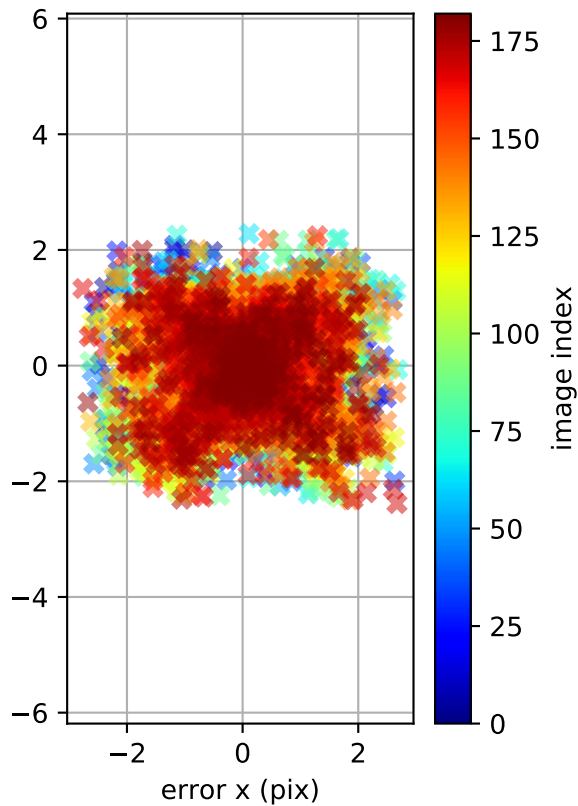
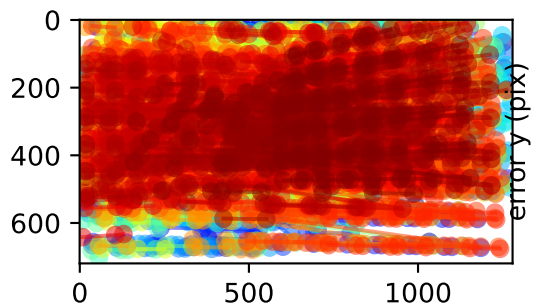
cam1: polar error



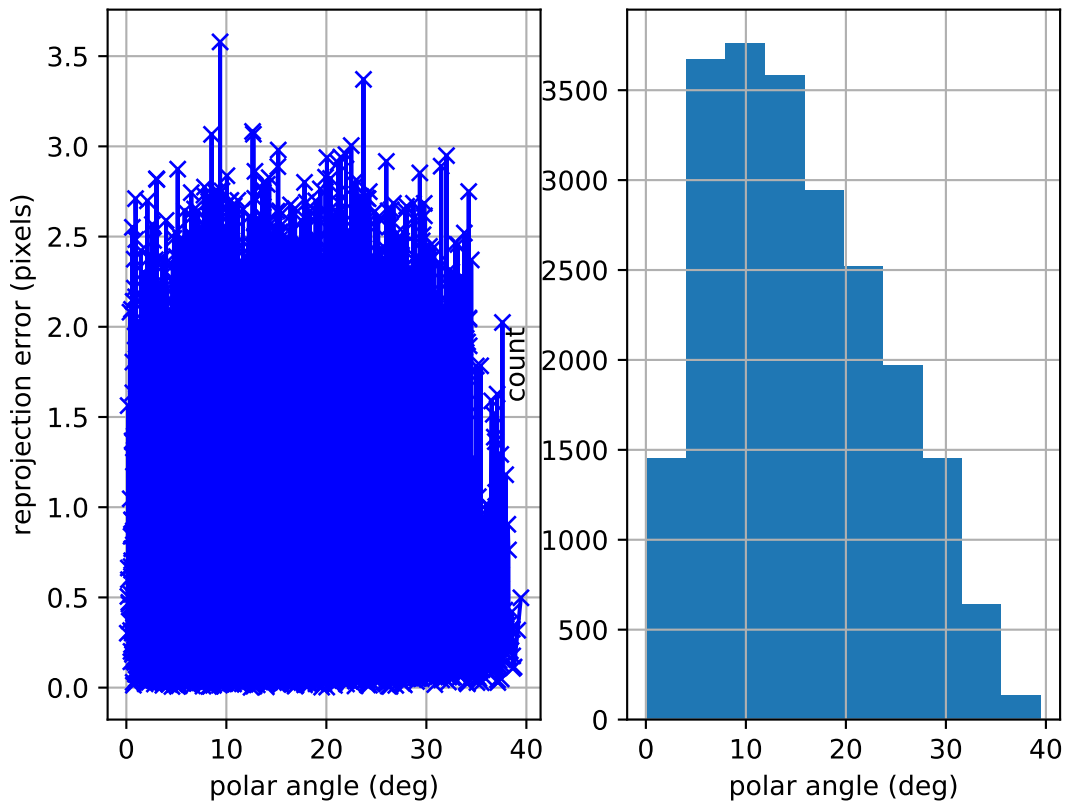
cam1: azimuthal error



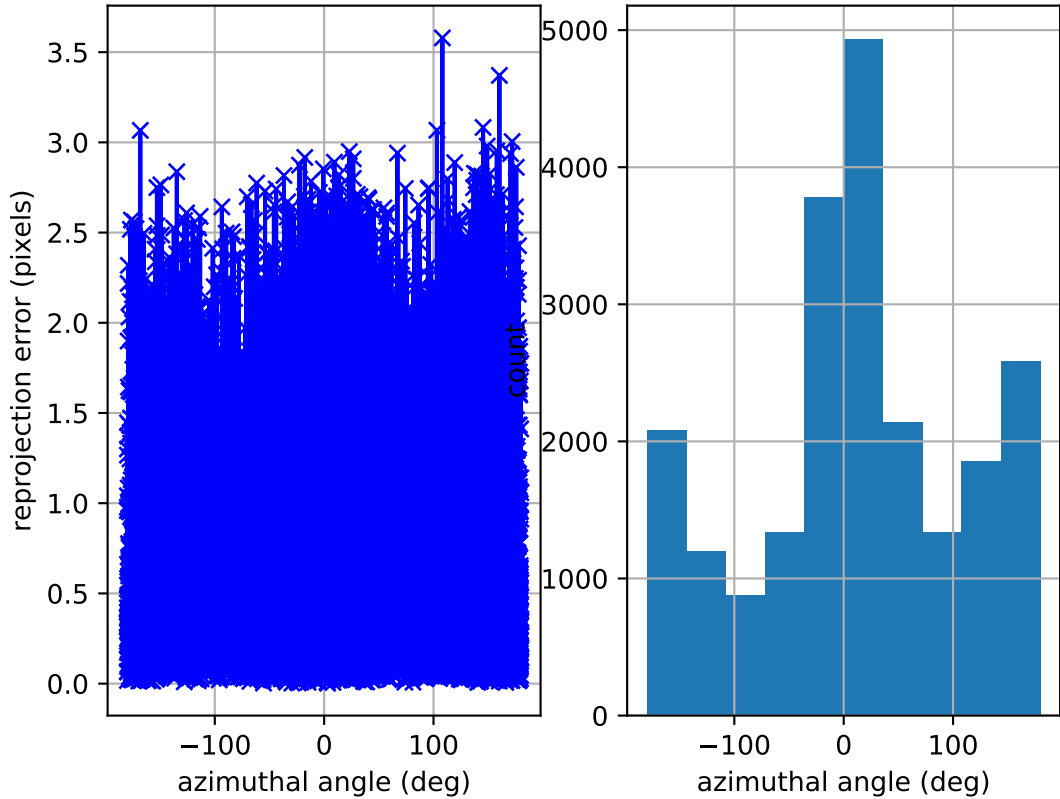
cam1: reprojection errors



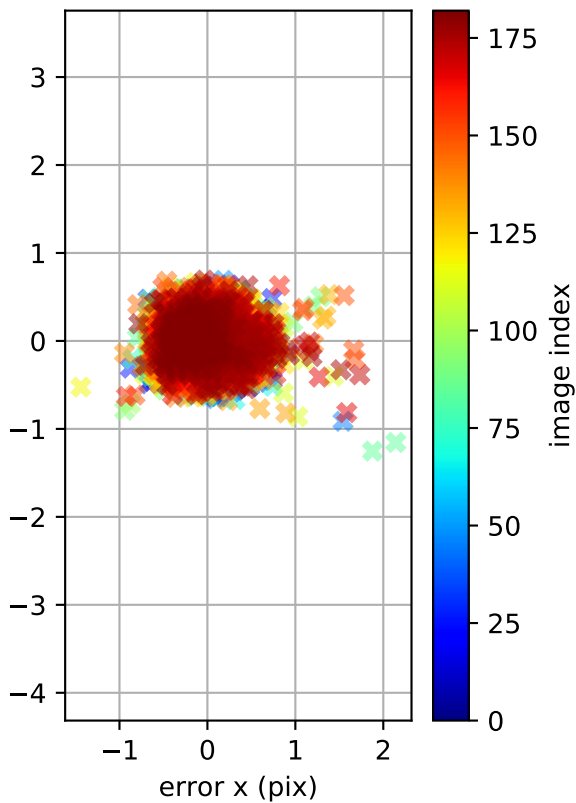
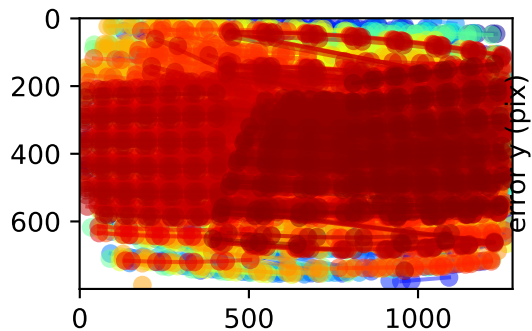
cam2: polar error



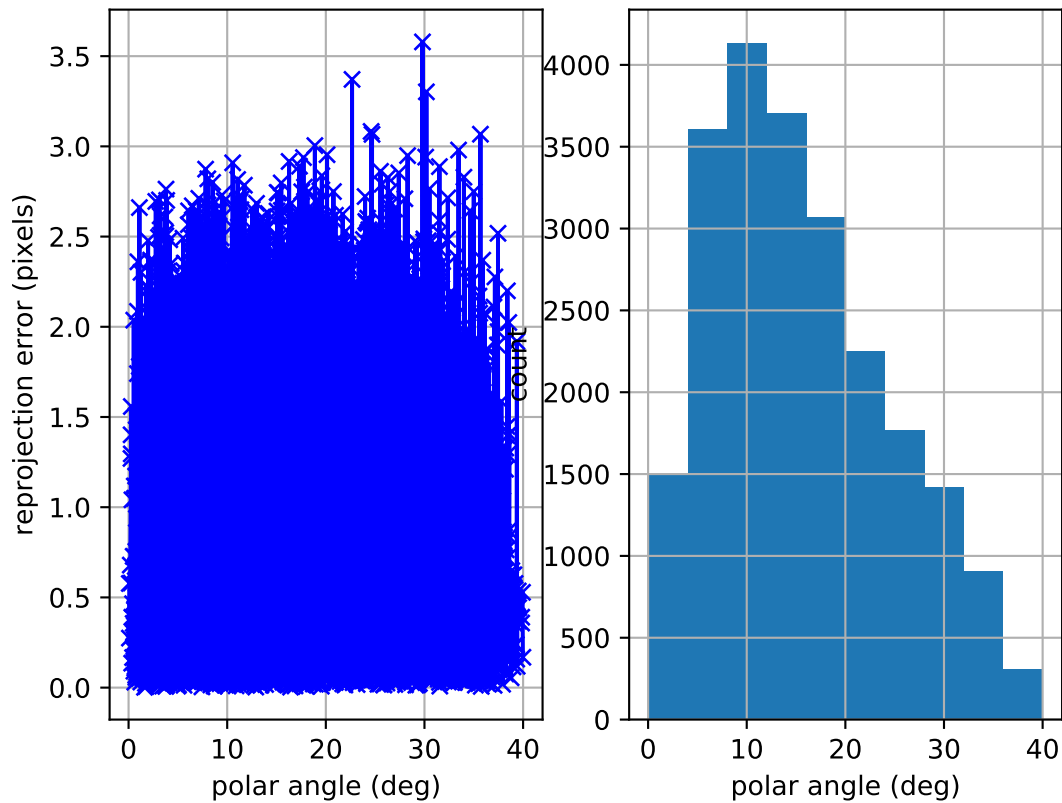
cam2: azimuthal error



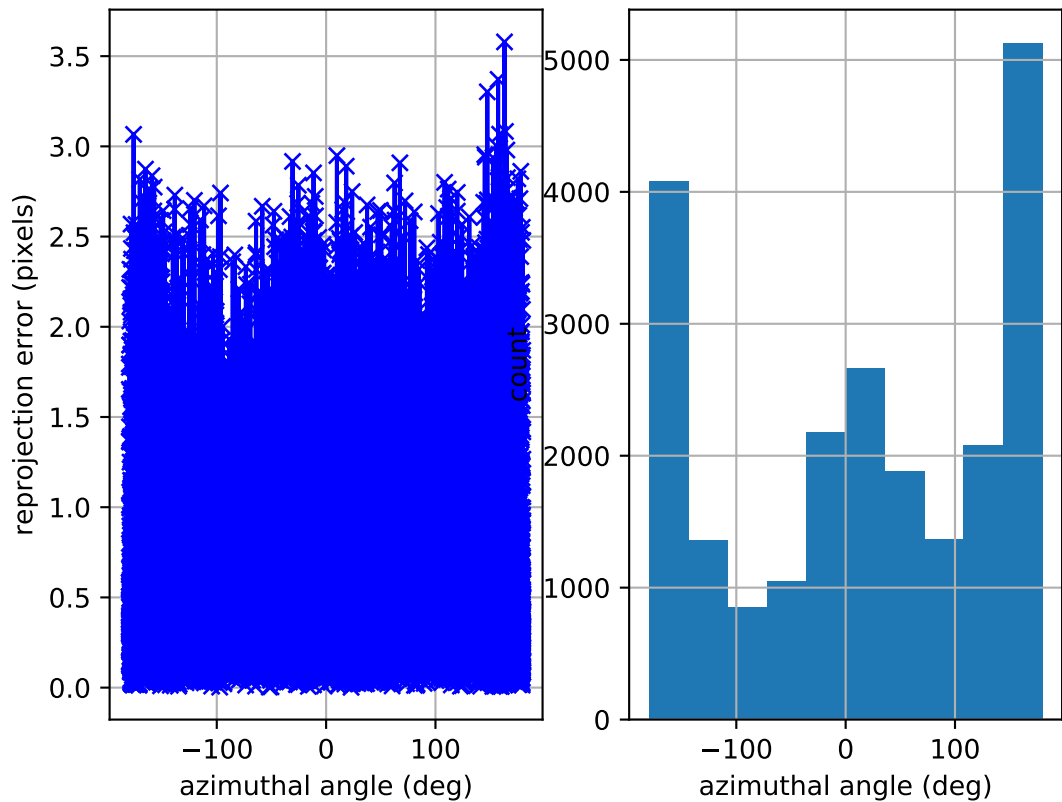
cam2: reprojection errors



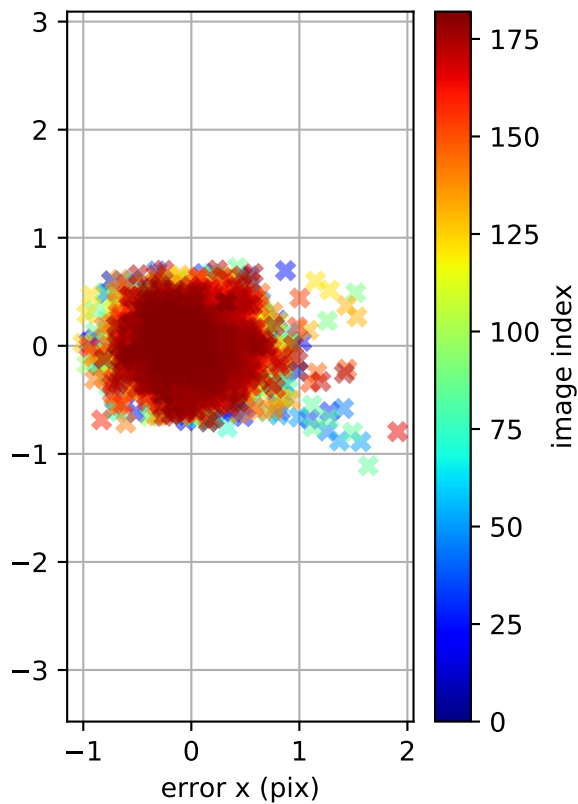
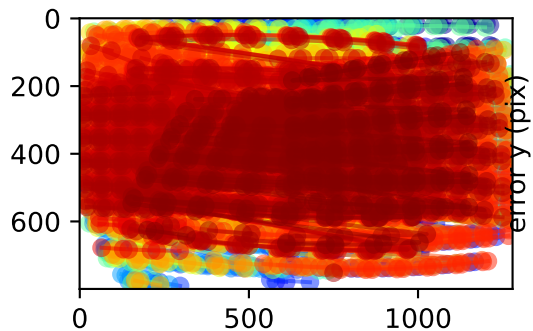
cam3: polar error



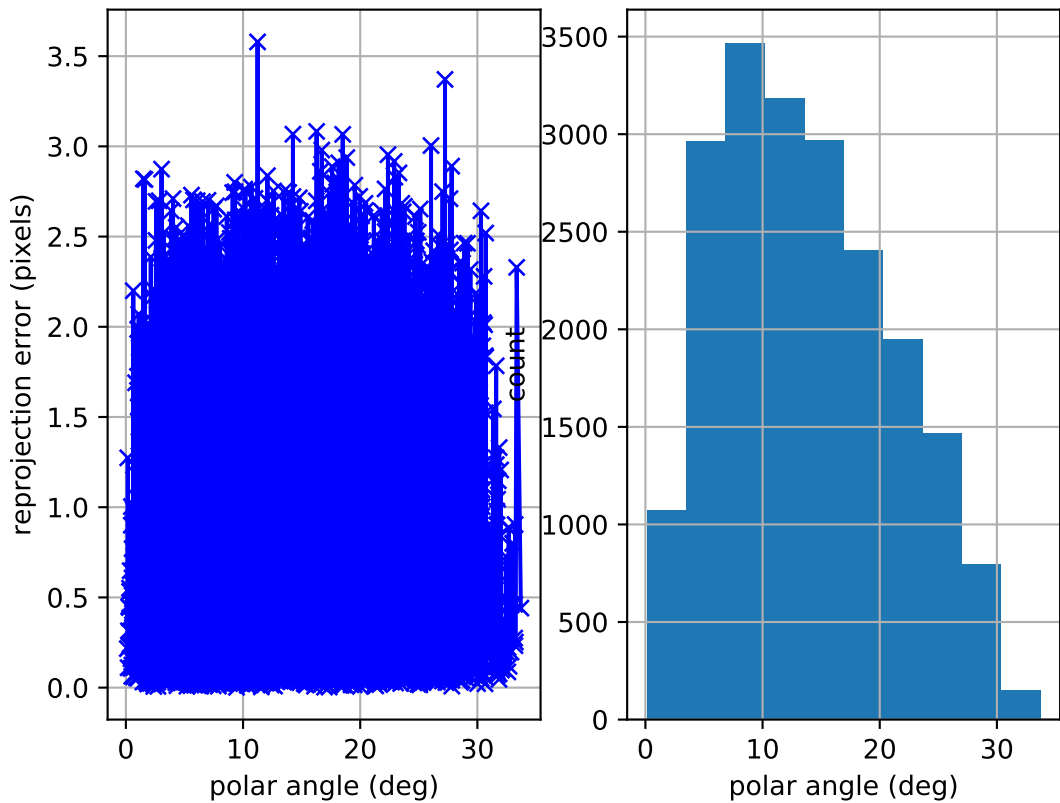
cam3: azimuthal error



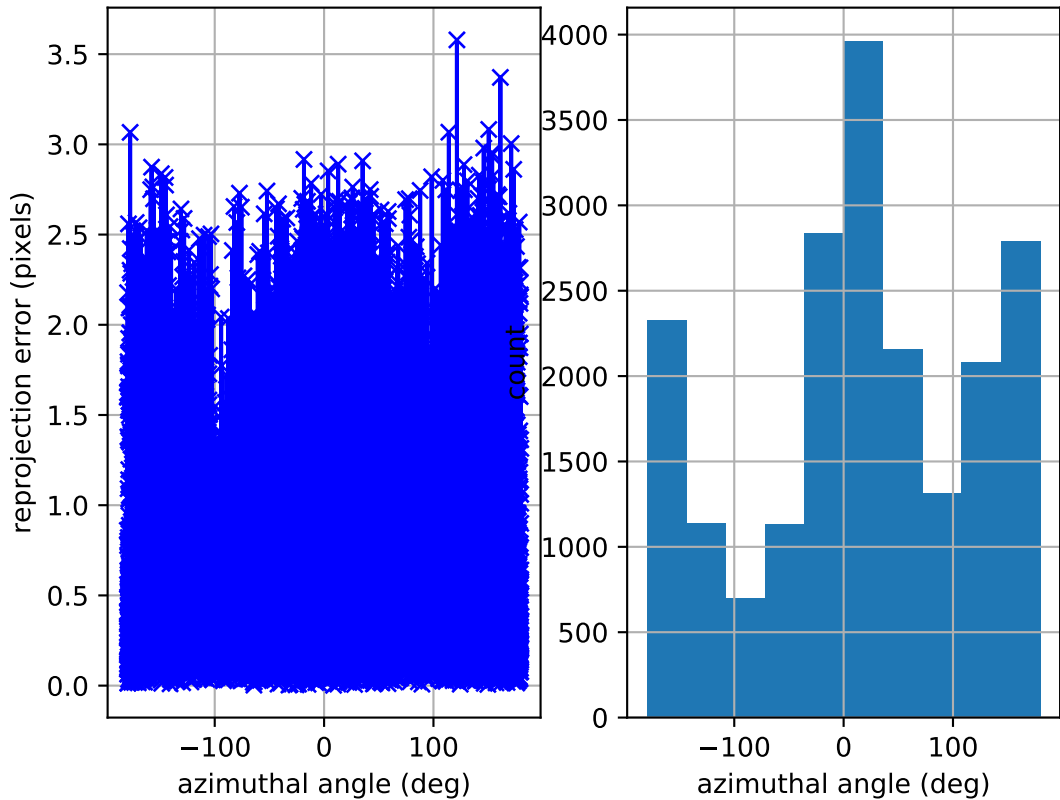
cam3: reprojection errors



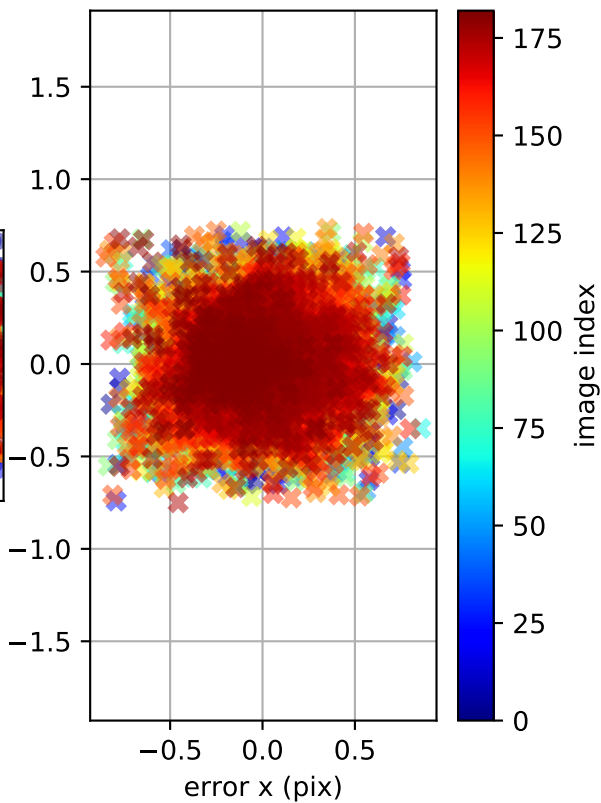
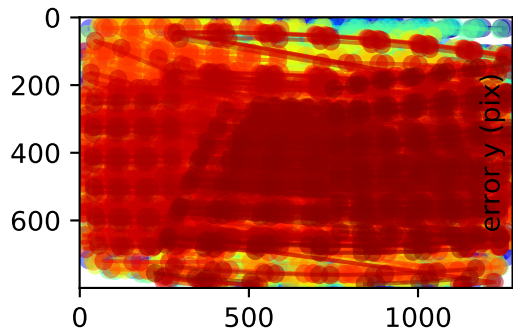
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

