

Calibration results

=====

Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04941636 0.08178983 -0.0000582 -0.0001781] +- [0.001041 0.00238817 0.0000816 0.00005097]
projection: [1031.36251068 1030.78952618 637.26408412 361.98841919] +- [0.13791997 0.14537049 0.00184319
0.09884325]

reprojection error: [0.000207, -0.000008] +- [0.664866, 0.551497]

cam1 (/prophesee/right/events):

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

distortion: [-0.05472234 0.08197468 0.00087733 0.0007608] +- [0.00103286 0.00233256 0.0000808 0.00005147]
projection: [1031.02877524 1030.23604974 639.24725777 364.25812599] +- [0.13930439 0.1461768 0.002258
0.10682414]

reprojection error: [0.000189, -0.000053] +- [0.707128, 0.628203]

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

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

distortion: [-0.39850765 0.16820812 0.00012013 0.00025356] +- [0.0005576 0.00105321 0.00005452 0.00003092]
projection: [1057.52090792 1057.40519649 677.5571956 334.73464168] +- [0.12837315 0.13186447 0.00884951
0.22187049]

reprojection error: [0.000212, -0.000157] +- [0.192552, 0.165991]

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

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

distortion: [-0.39446382 0.15643768 0.00001961 0.00078667] +- [0.00043781 0.00070935 0.00005273 0.00003108]
projection: [1052.08696961 1052.15969608 674.87377882 327.38632532] +- [0.12353595 0.12562212 0.0056424
0.21253646]

reprojection error: [0.000281, -0.000211] +- [0.218501, 0.177603]

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

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

distortion: [-0.41812382 0.19328243 0.00026235 -0.00036289] +- [0.00077594 0.00202979 0.00005278 0.00003341]
projection: [1263.54107808 1263.16870011 656.34536883 365.62726239] +- [0.1273478 0.13010426 0.00372214
0.11376348]

reprojection error: [0.000110, -0.000031] +- [0.210774, 0.185494]

baseline T_1_0:

q: [-0.00003892 0.00190004 -0.0003024 0.99999815] +- [0.00012285 0.00005944 0.00004195]

t: [-0.12008191 0.00102988 -0.00048214] +- [0.0000303 0.00003103 0.00009304]

baseline T_2_1:

q: [-0.00033207 -0.00370517 -0.00485432 0.9999813] +- [0.00027412 0.00005605 0.00003795]

t: [0.12008028 0.06921603 0.00416029] +- [0.00002794 0.00002854 0.00009178]

baseline T_3_2:

q: [-0.00008969 0.0001398 0.00038571 0.99999991] +- [0.00030609 0.00005002 0.00003287]

t: [-0.12008148 -0.00010244 0.00036673] +- [0.00002575 0.00002545 0.00008709]

baseline T_4_3:

q: [0.00217091 0.00228342 0.00029142 0.99999499] +- [0.00026422 0.00004556 0.00003163]

t: [0.08890692 0.00620771 0.00312582] +- [0.00002402 0.0000236 0.00008177]

Target configuration

=====

Type: aprilgrid

Tags:

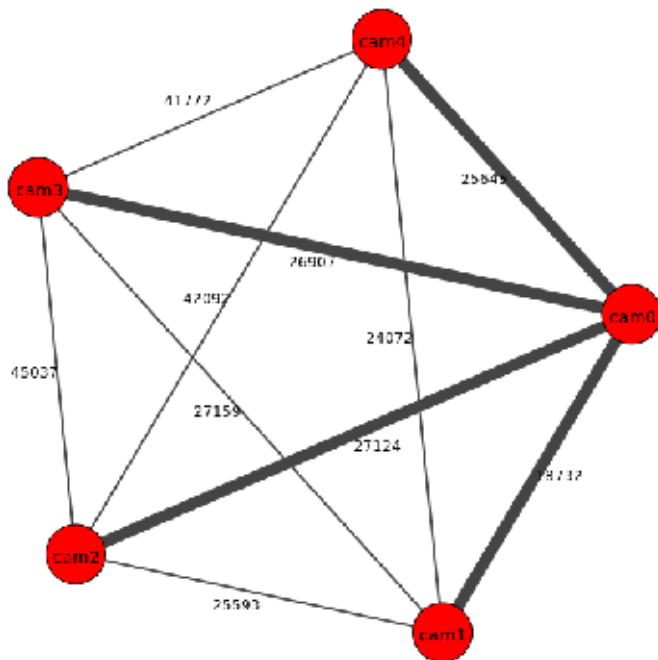
Rows: 5

Cols: 7

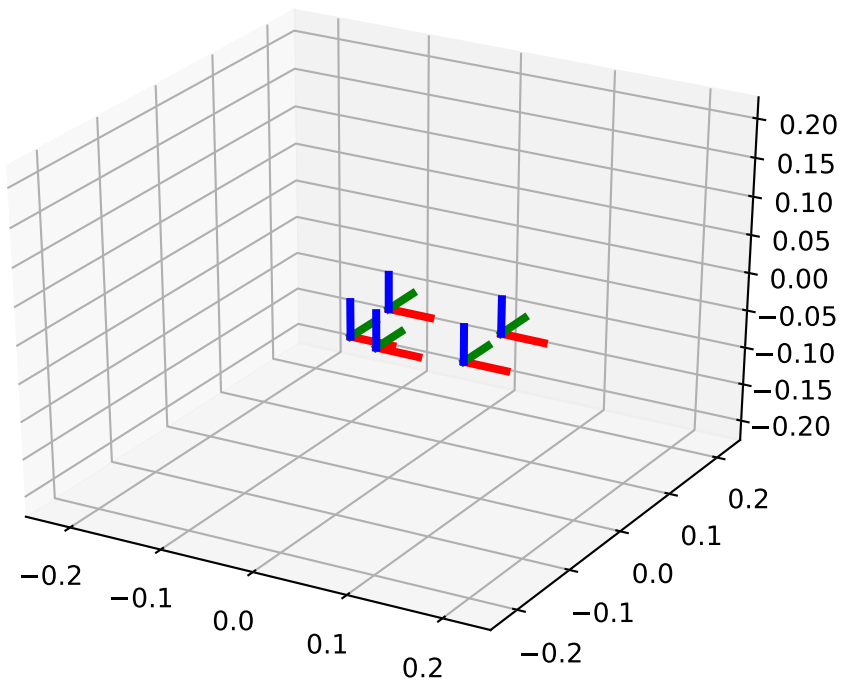
Size: 0.04 [m]

Spacing 0.01 [m]

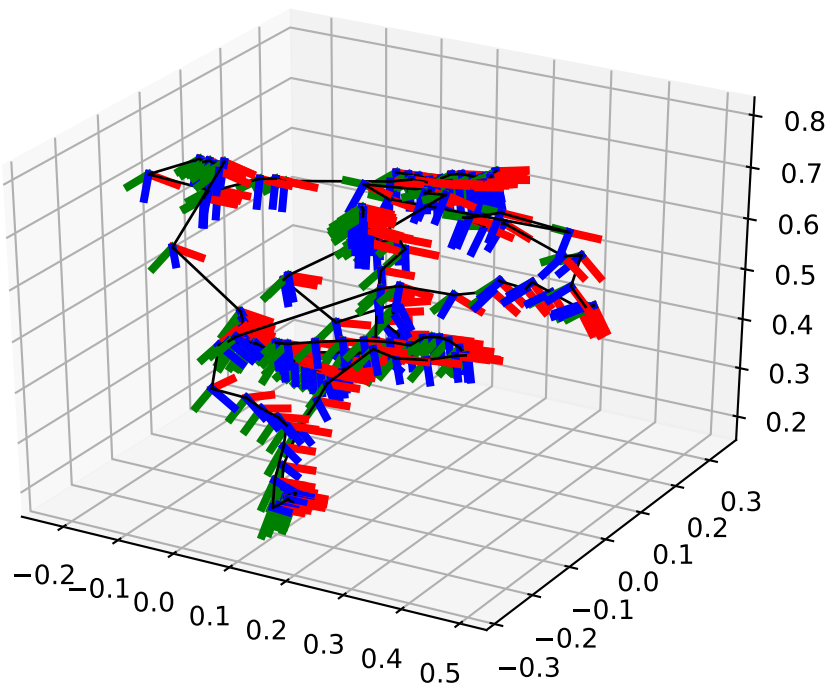
Inter-camera observations graph (edge weight=#mutual obs.)



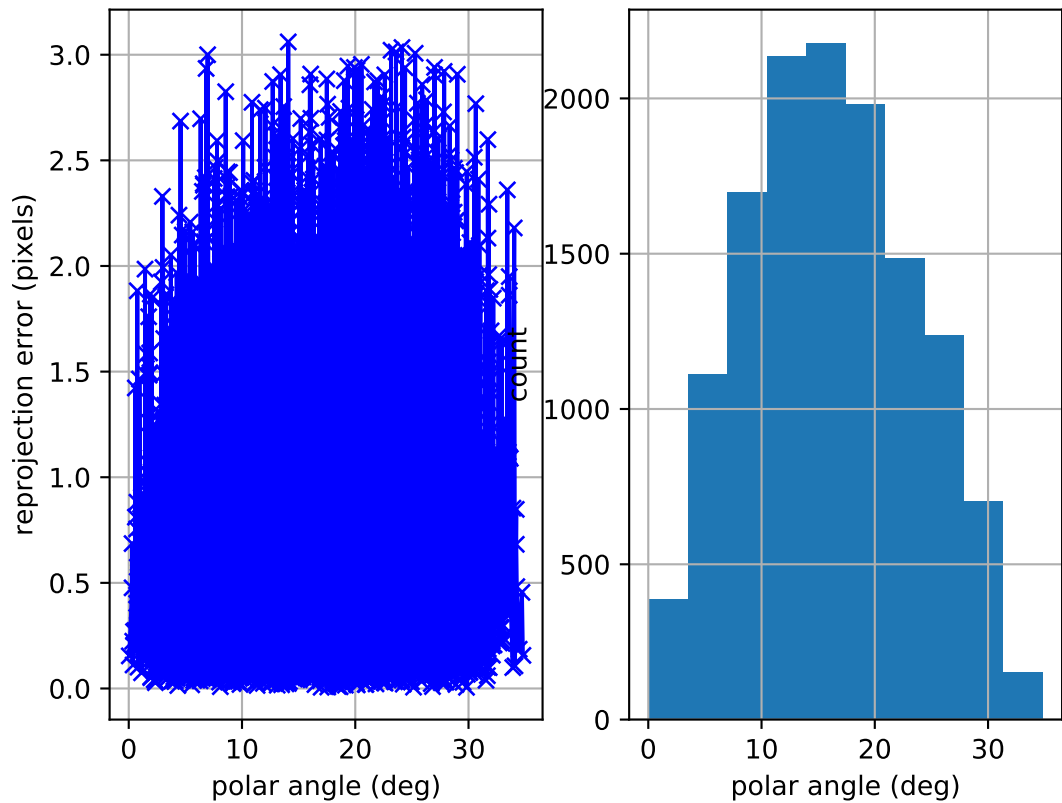
camera system



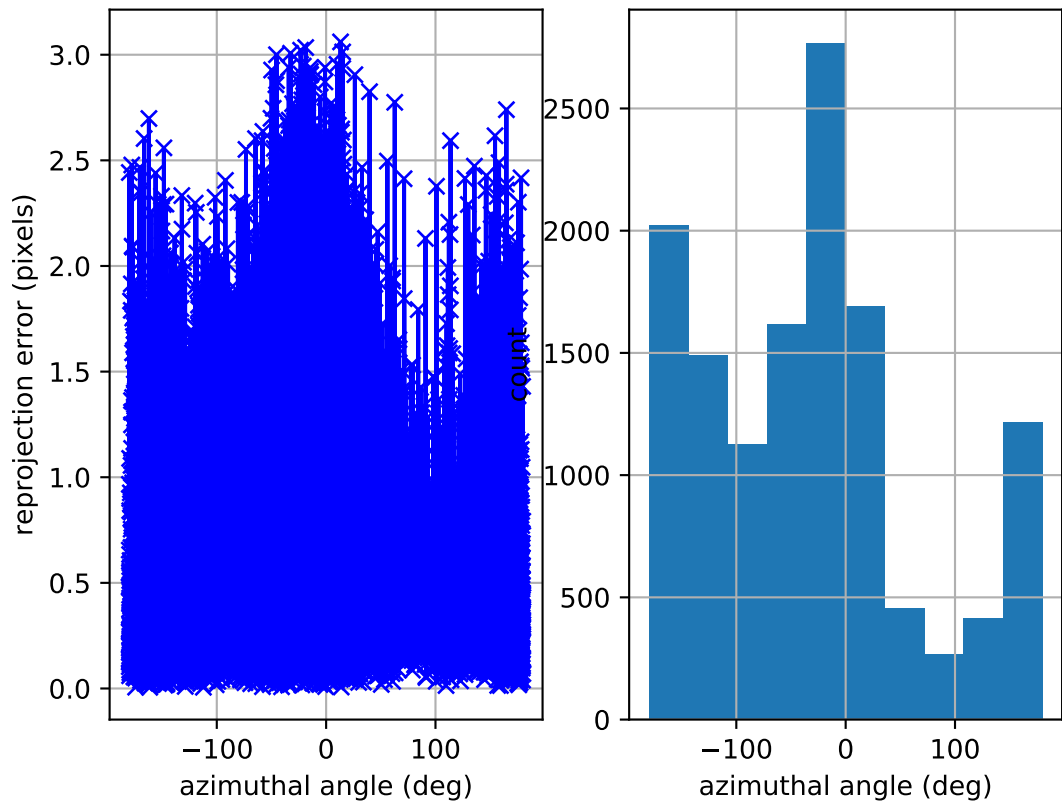
cam0: estimated poses



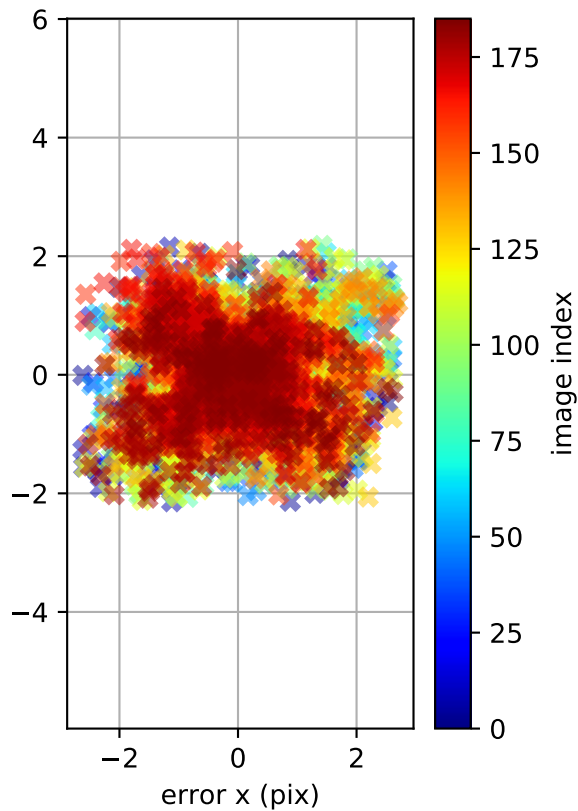
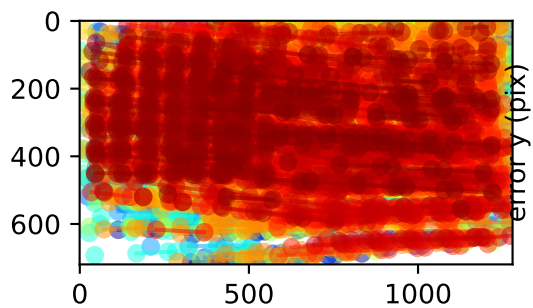
cam0: polar error



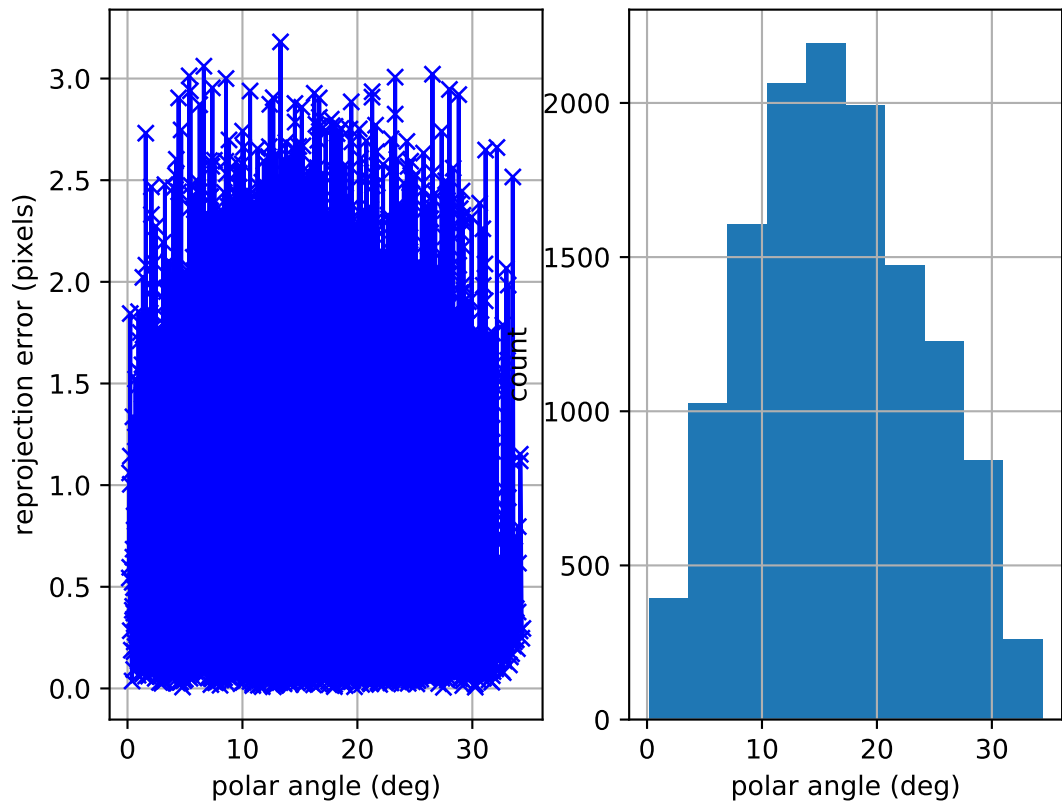
cam0: azimuthal error



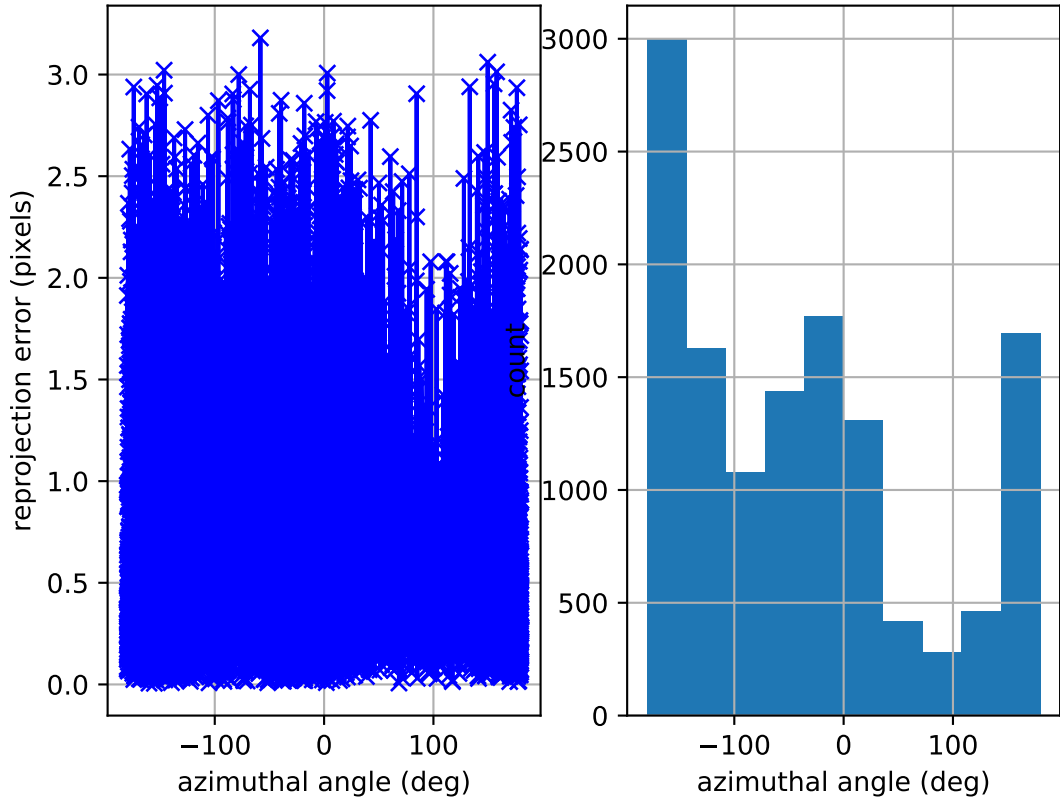
cam0: reprojection errors



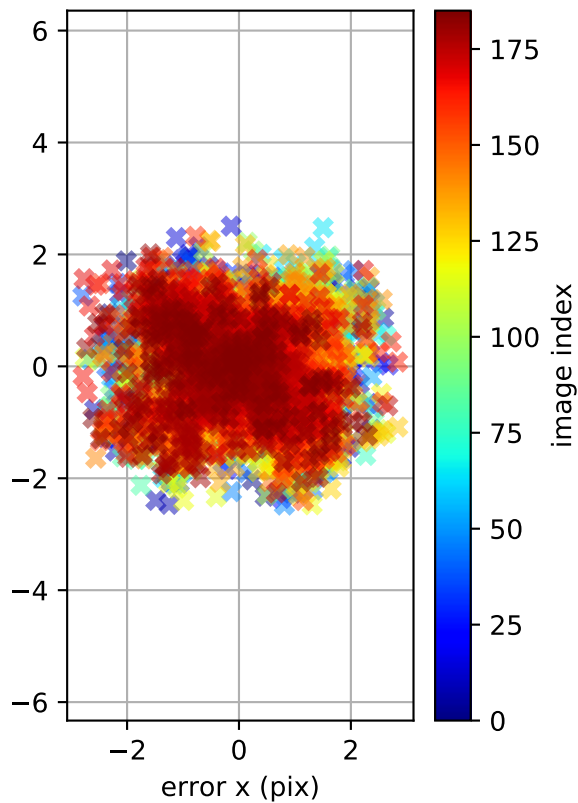
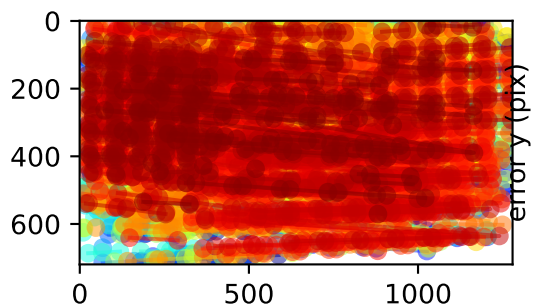
cam1: polar error



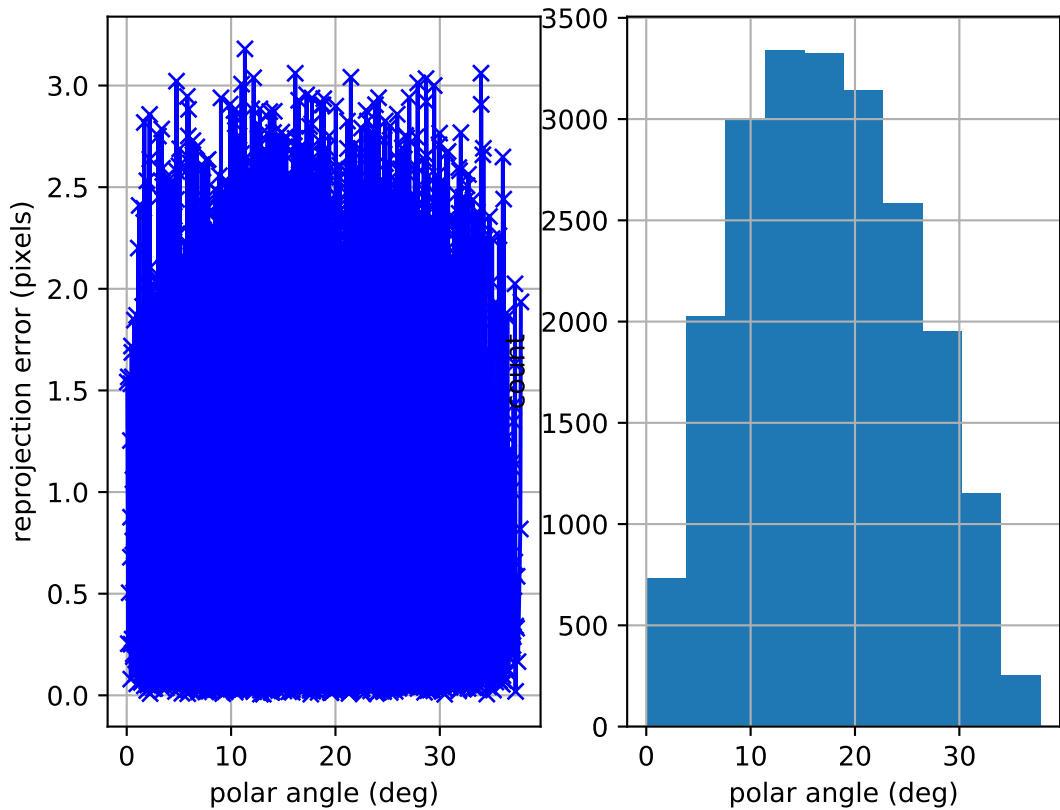
cam1: azimuthal error



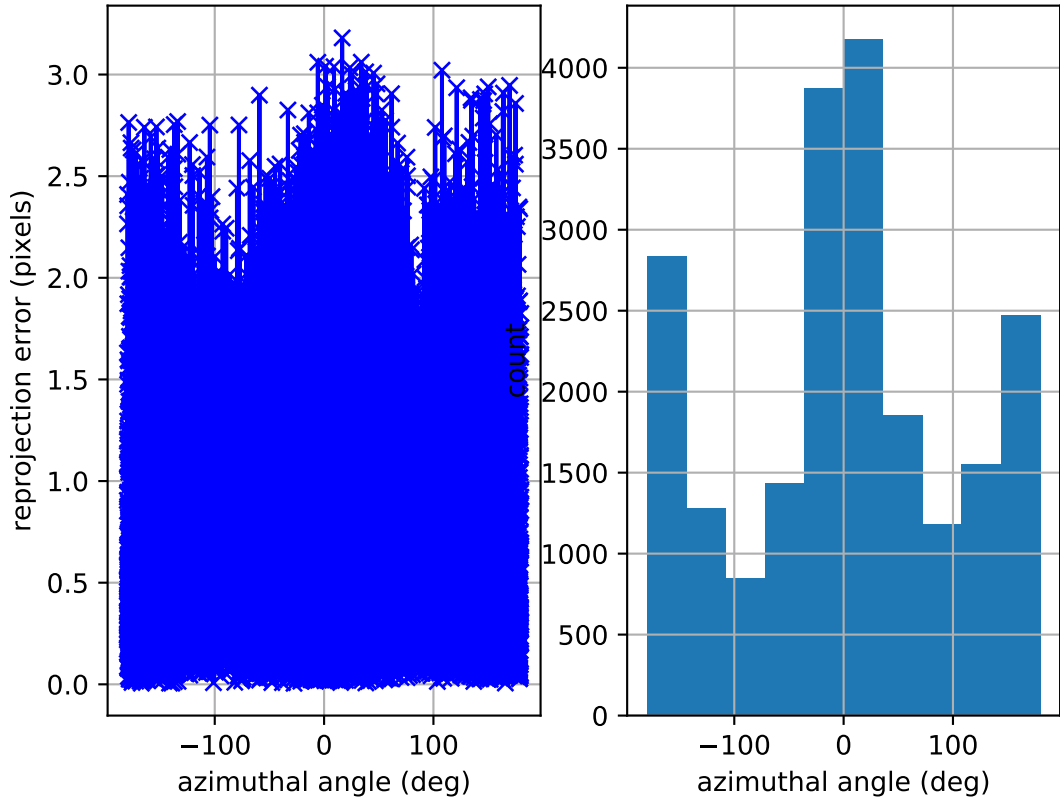
cam1: reprojection errors



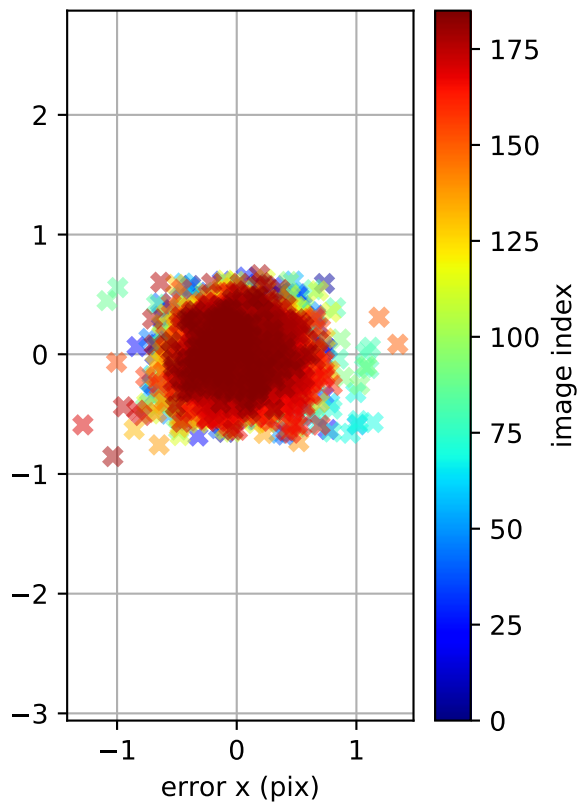
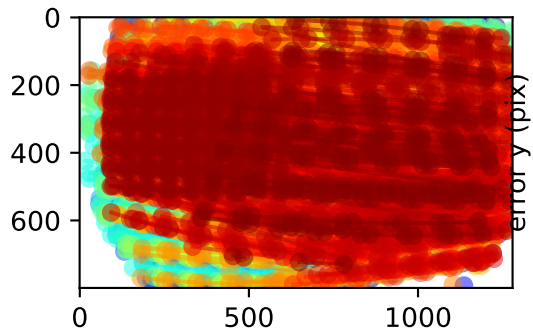
cam2: polar error



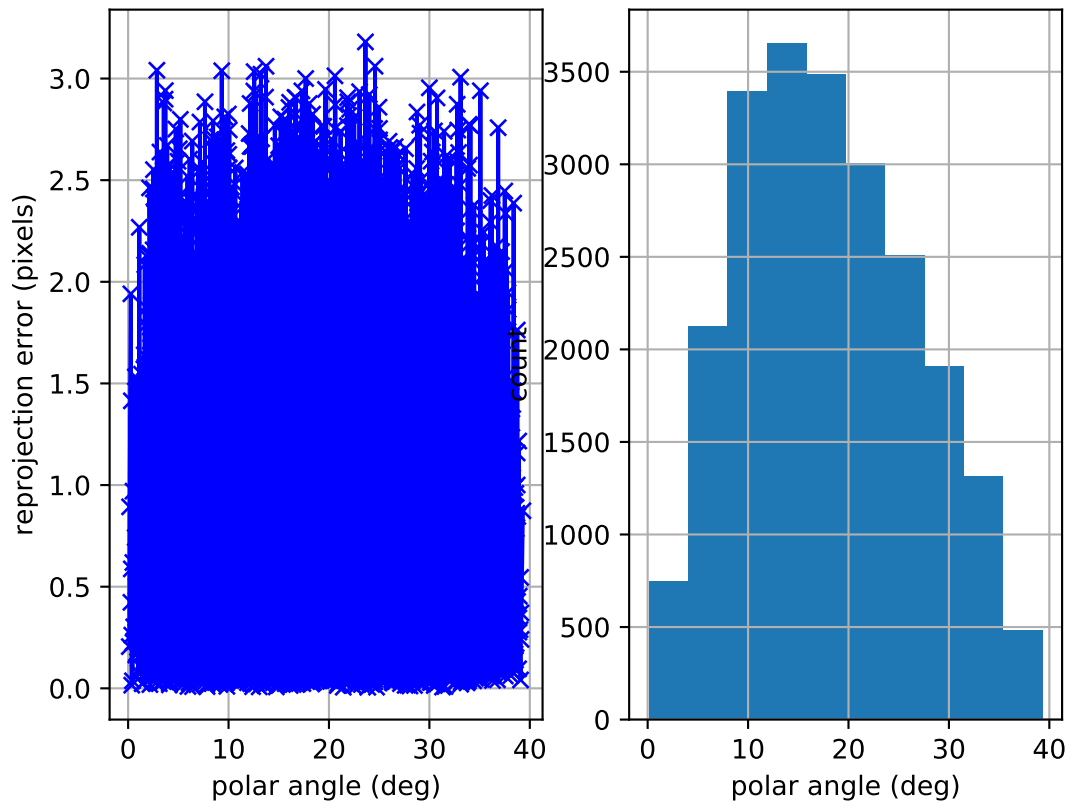
cam2: azimuthal error



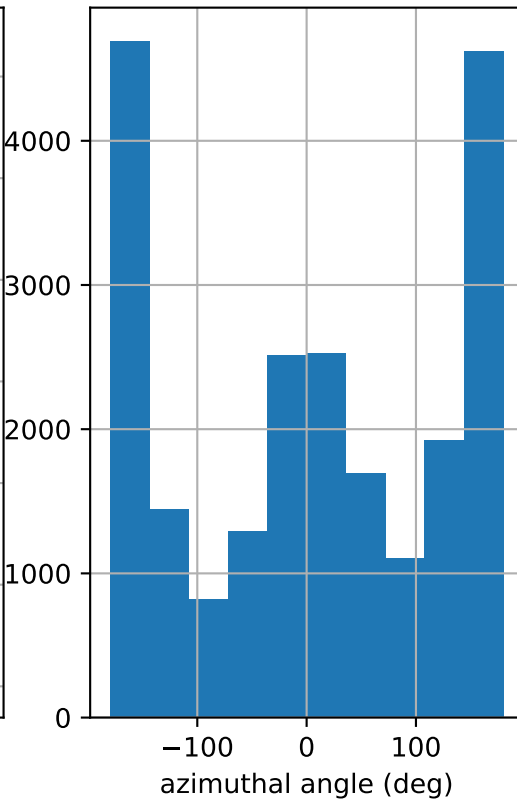
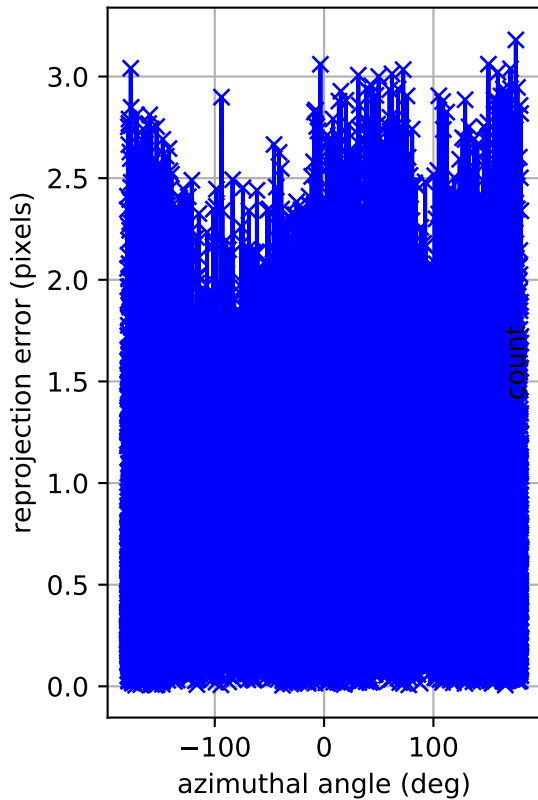
cam2: reprojection errors



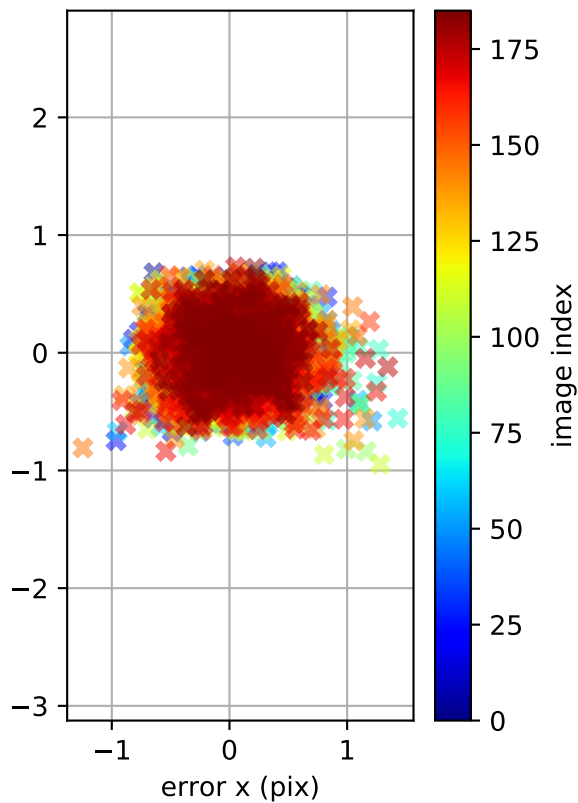
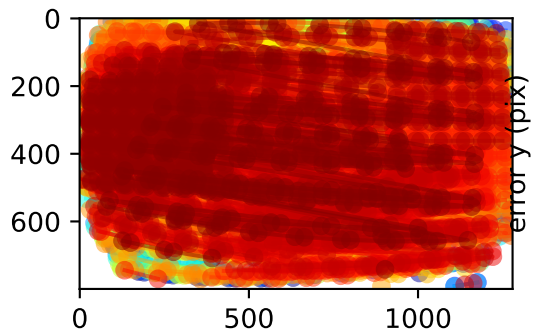
cam3: polar error



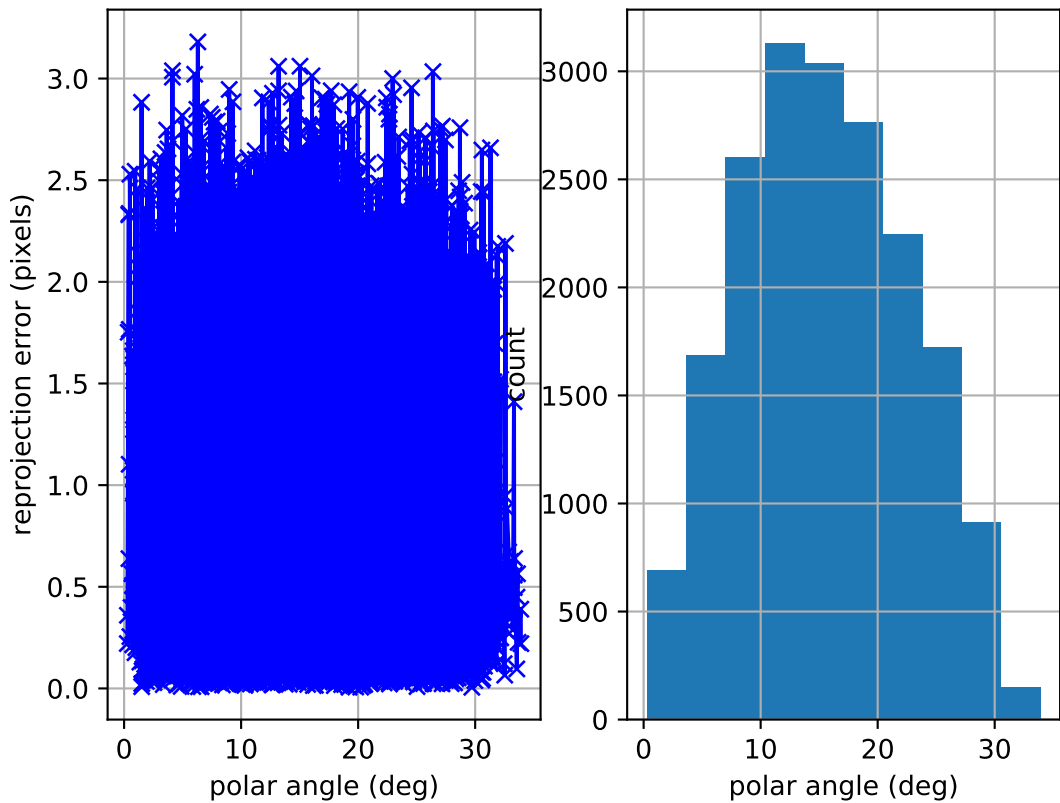
cam3: azimuthal error



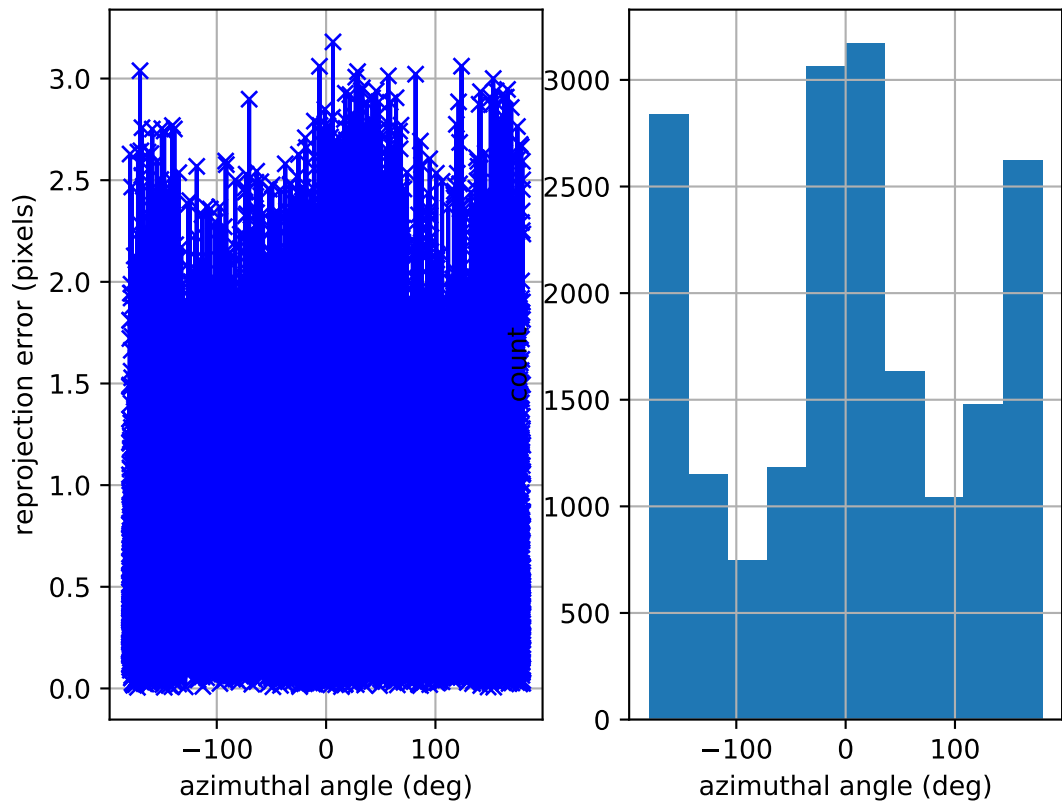
cam3: reprojection errors



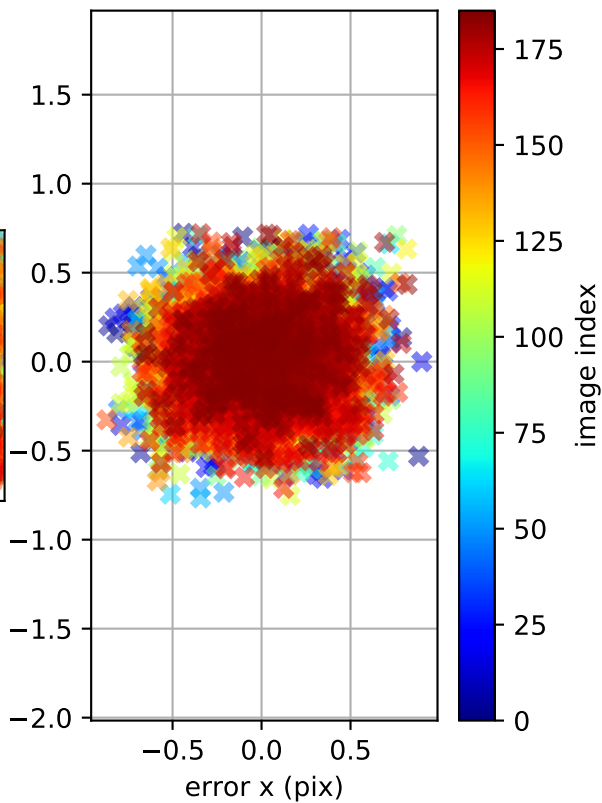
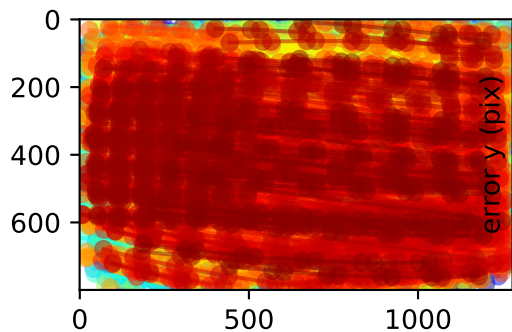
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

