

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.0485709 0.08682549 -0.0002699 -0.00056754] +- [0.00103569 0.00235976 0.00008917 0.00005798]

projection: [1033.22946467 1032.37940162 637.14899526 359.16366857] +- [0.14657809 0.15262248 0.00608581 0.10351982]

reprojection error: [0.000195, -0.000036] +- [0.434500, 0.398130]

cam1 (/prophesee/right/events):

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

distortion: [-0.05313583 0.08425457 0.00086073 0.00064893] +- [0.00101045 0.0022585 0.00008868 0.0000546]

projection: [1032.7719854 1031.93236836 639.10742672 362.60248038] +- [0.14402661 0.15073124 0.00561509 0.11842715]

reprojection error: [0.000169, -0.000062] +- [0.462674, 0.412125]

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

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

distortion: [-0.39980897 0.1711037 0.00054394 -0.0001217] +- [0.00061968 0.00122472 0.00006477 0.00003911]

projection: [1058.92079902 1058.44572533 679.02889394 332.88134806] +- [0.1348284 0.13690931 0.01024417 0.23578131]

reprojection error: [0.000121, -0.000100] +- [0.191030, 0.178663]

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

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

distortion: [-0.39820056 0.16265832 0.00045042 0.00056673] +- [0.00051346 0.00089458 0.00006213 0.0000351]

projection: [1054.1980728 1053.88534494 675.64051577 325.23968865] +- [0.13144664 0.13666058 0.01258591 0.22391447]

reprojection error: [0.000125, -0.000145] +- [0.199387, 0.179434]

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

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

distortion: [-0.41983376 0.19662196 0.00087533 -0.00064392] +- [0.0008358 0.0021892 0.00006484 0.00004023]

projection: [1266.10199406 1265.1295111 657.93873946 362.98263614] +- [0.13963207 0.13996335 0.00324358 0.09662514]

reprojection error: [-0.000047, -0.000046] +- [0.214807, 0.215962]

baseline T_1_0:

q: [-0.00054919 0.00227043 -0.00022891 0.99999725] +- [0.00010785 0.00005723 0.00004117]

t: [-0.12007048 0.00095088 -0.00051932] +- [0.00003837 0.00003708 0.00013433]

baseline T_2_1:

q: [-0.00010448 -0.00312316 -0.00494183 0.99998291] +- [0.0002903 0.00005371 0.0000384]

t: [0.12023085 0.06906789 0.00363918] +- [0.00003562 0.00003576 0.00012944]

baseline T_3_2:

q: [-0.00000042 0.00003677 0.00040408 0.99999992] +- [0.00032671 0.00005353 0.00003394]

t: [-0.11996243 -0.00007122 0.00062883] +- [0.00003315 0.00003283 0.00012815]

baseline T_4_3:

q: [0.00216039 0.00233352 0.00023967 0.99999491] +- [0.00026223 0.00004919 0.00003207]

t: [0.08880781 0.00624181 0.00341574] +- [0.00003152 0.0000308 0.00011861]

Target configuration

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Type: aprilgrid

Tags:

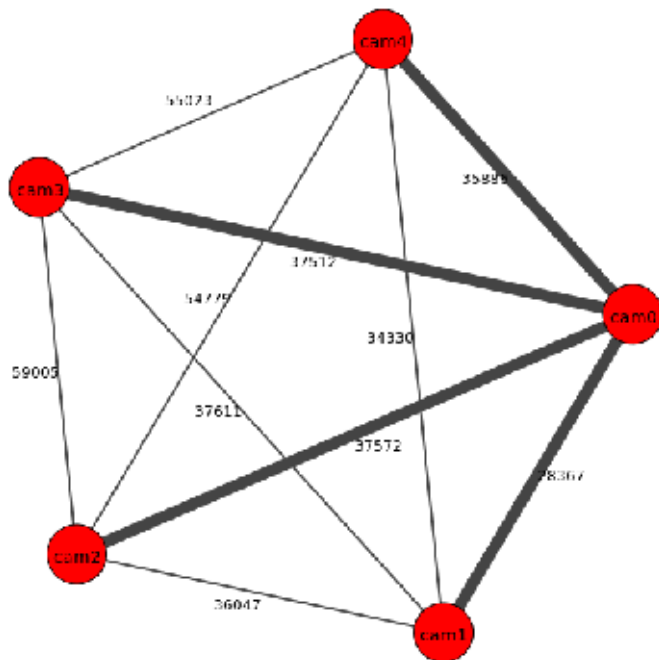
Rows: 5

Cols: 7

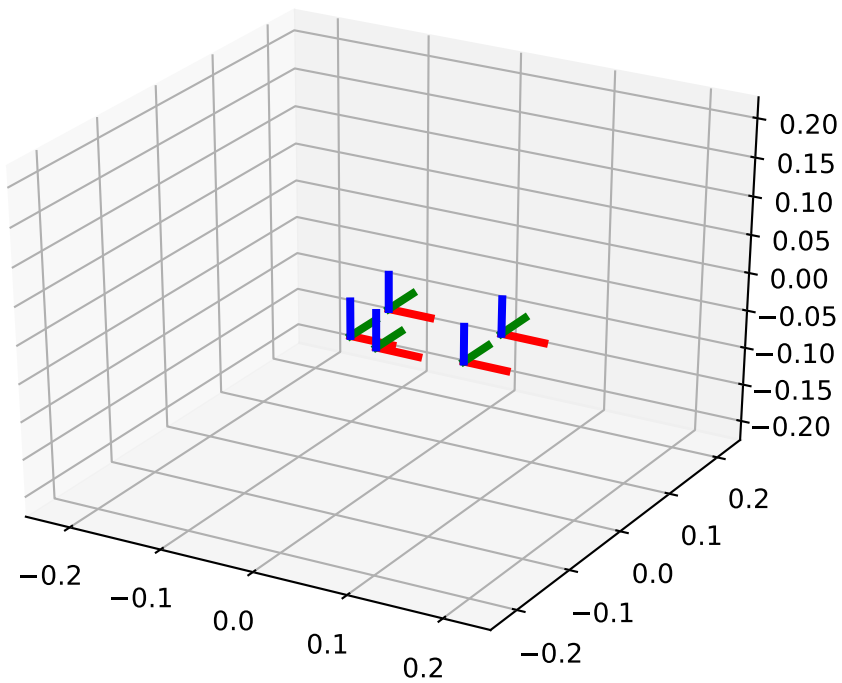
Size: 0.04 [m]

Spacing 0.01 [m]

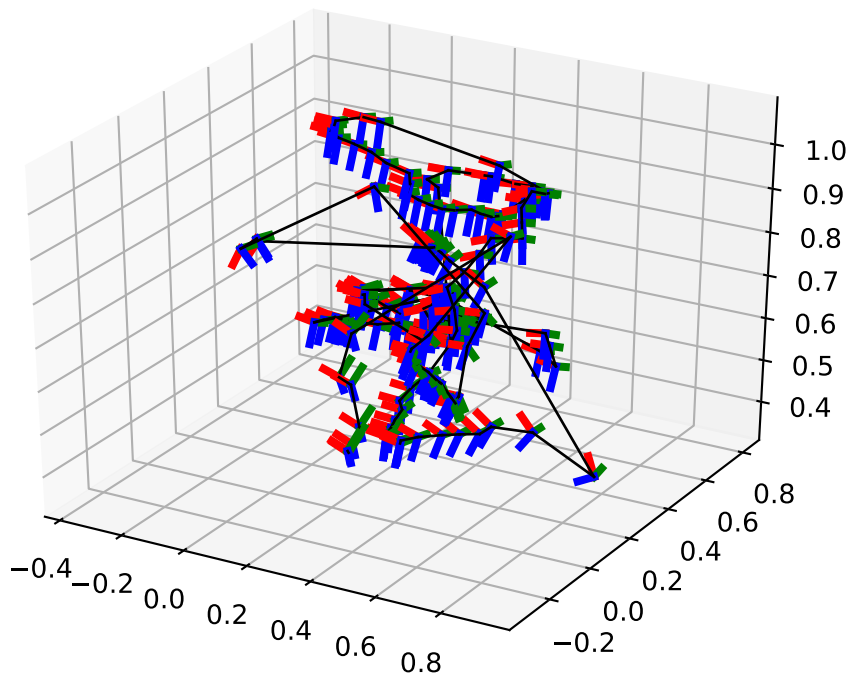
Inter-camera observations graph (edge weight=#mutual obs.)



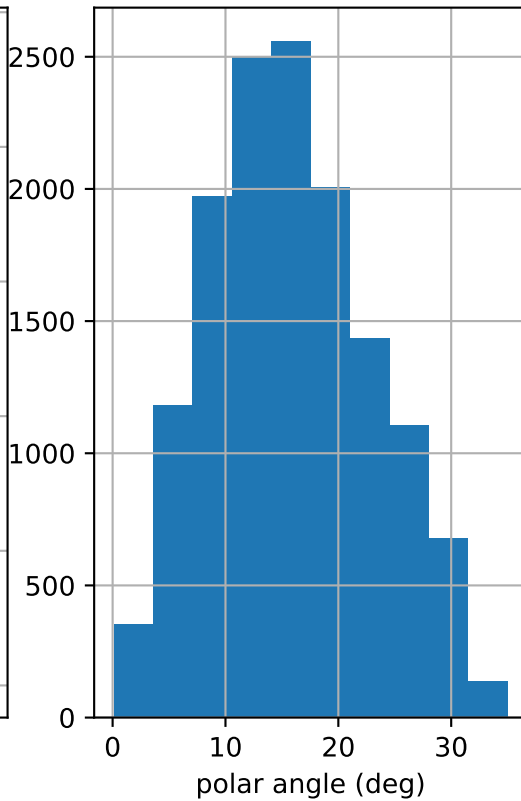
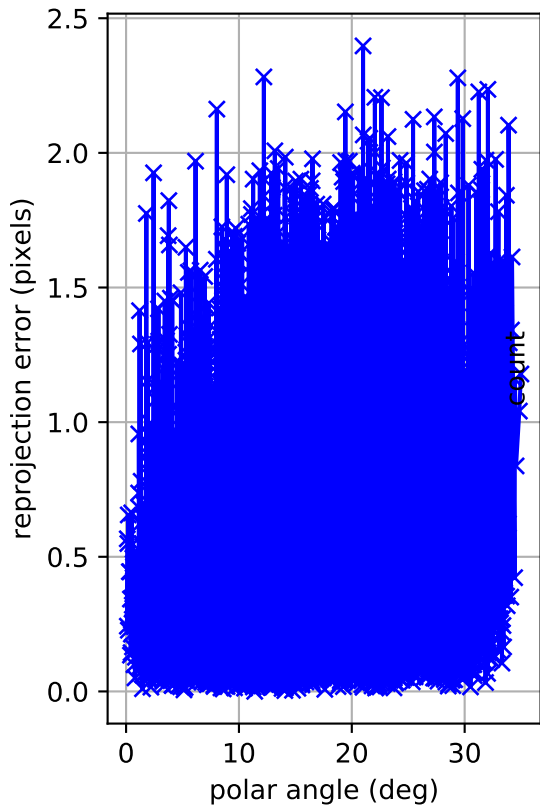
camera system



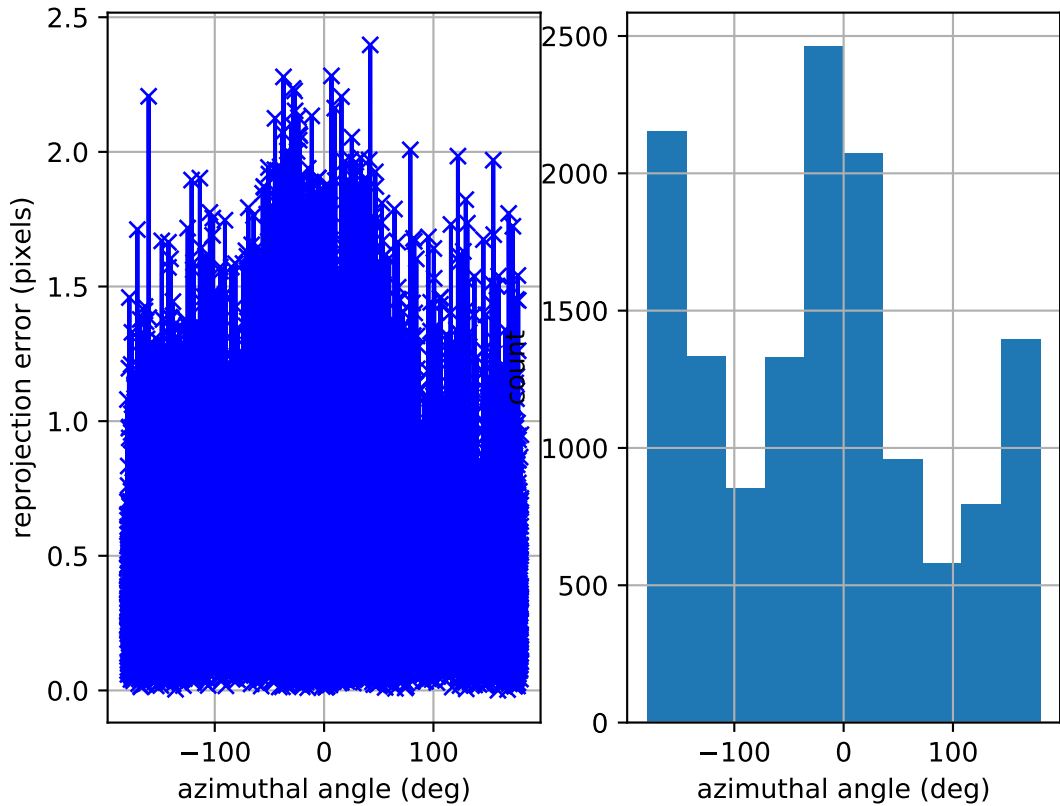
cam0: estimated poses



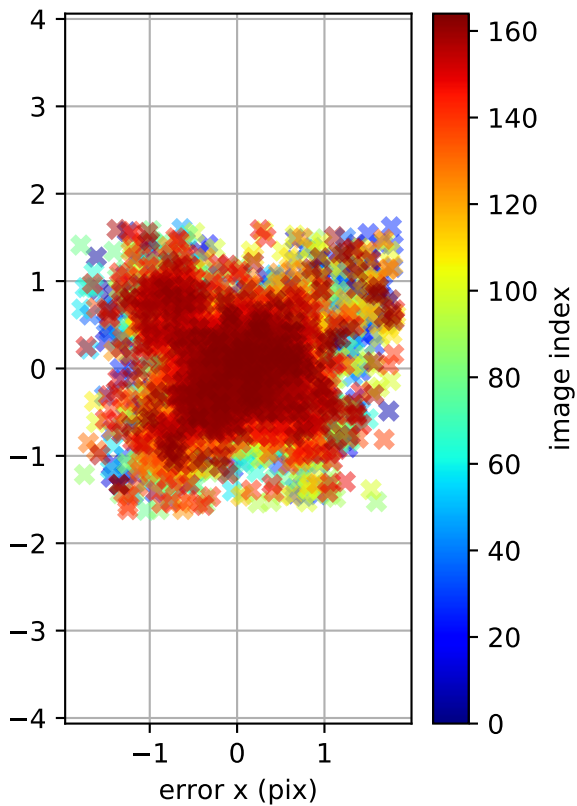
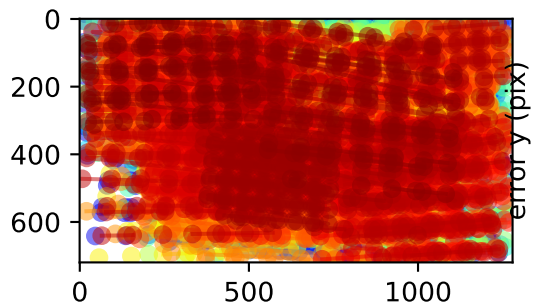
cam0: polar error



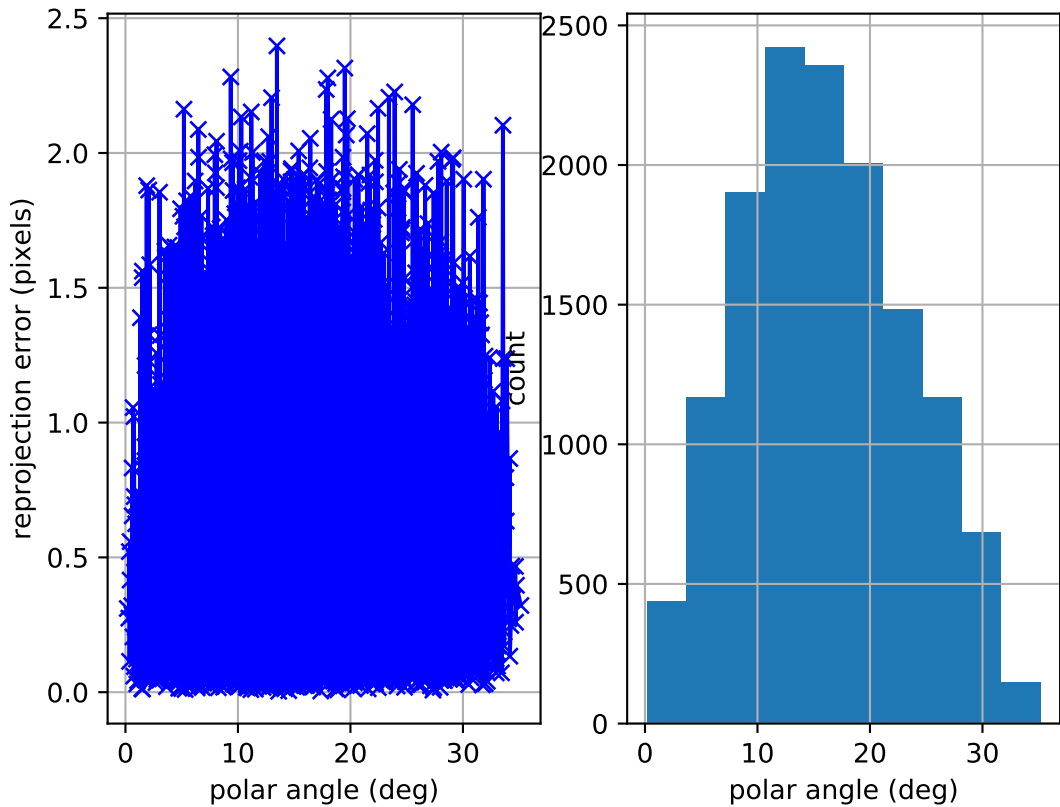
cam0: azimuthal error



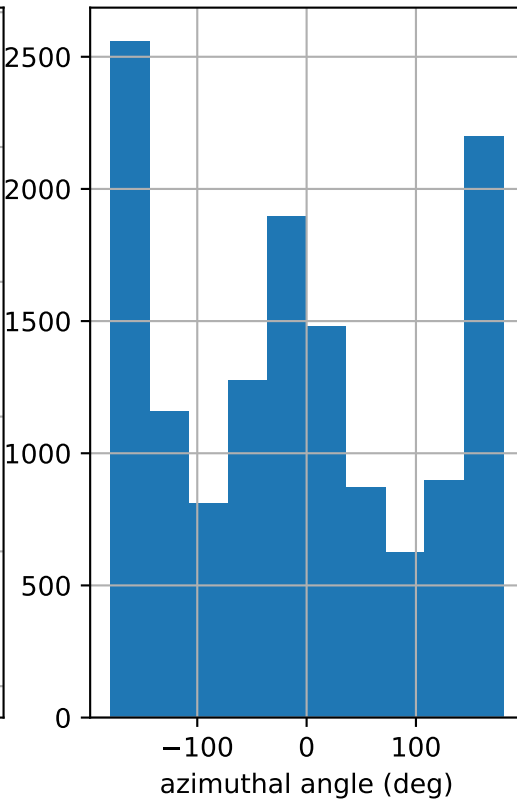
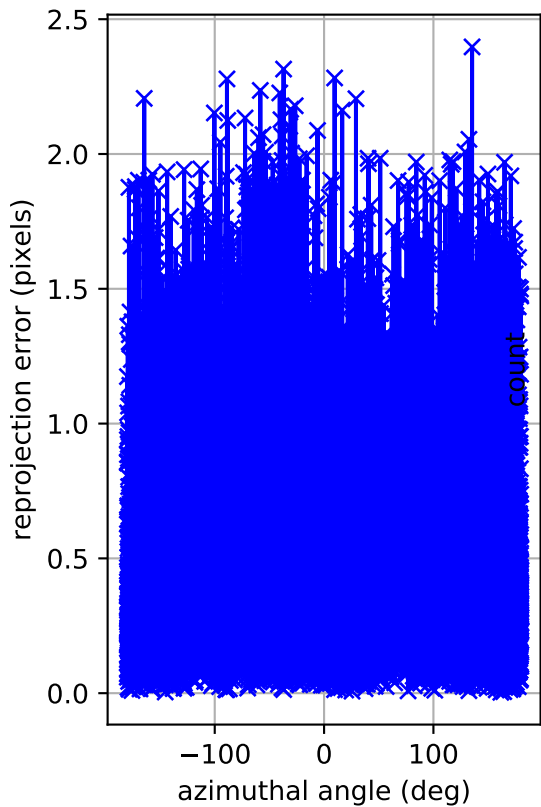
cam0: reprojection errors



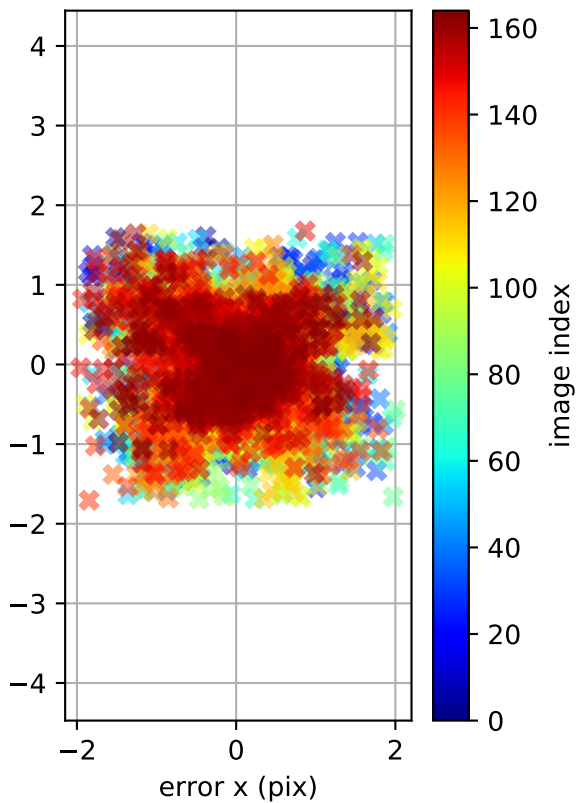
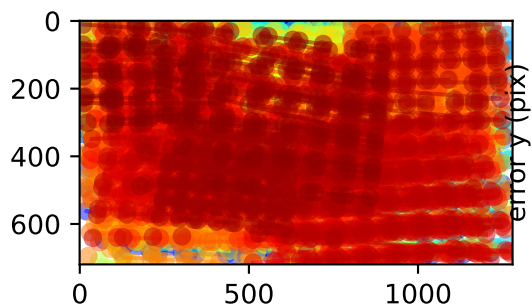
cam1: polar error



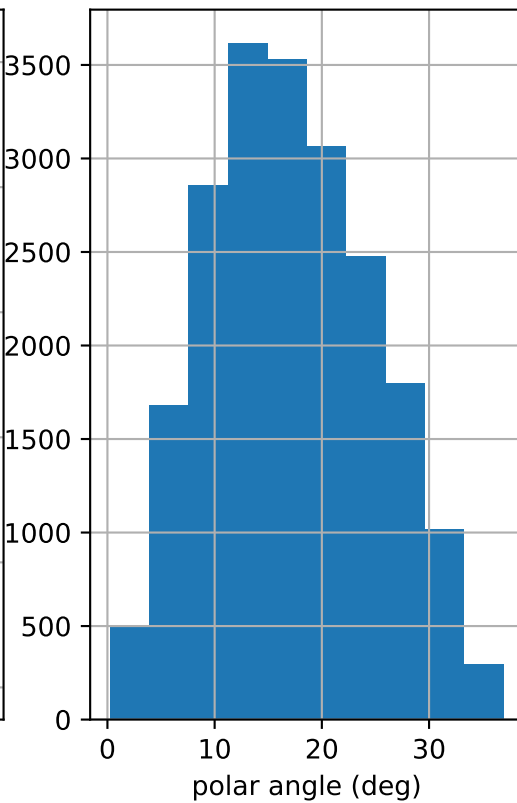
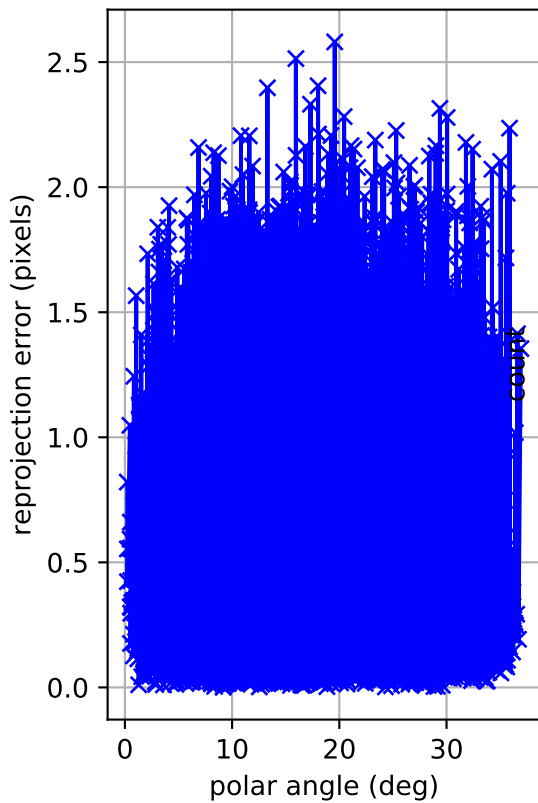
cam1: azimuthal error



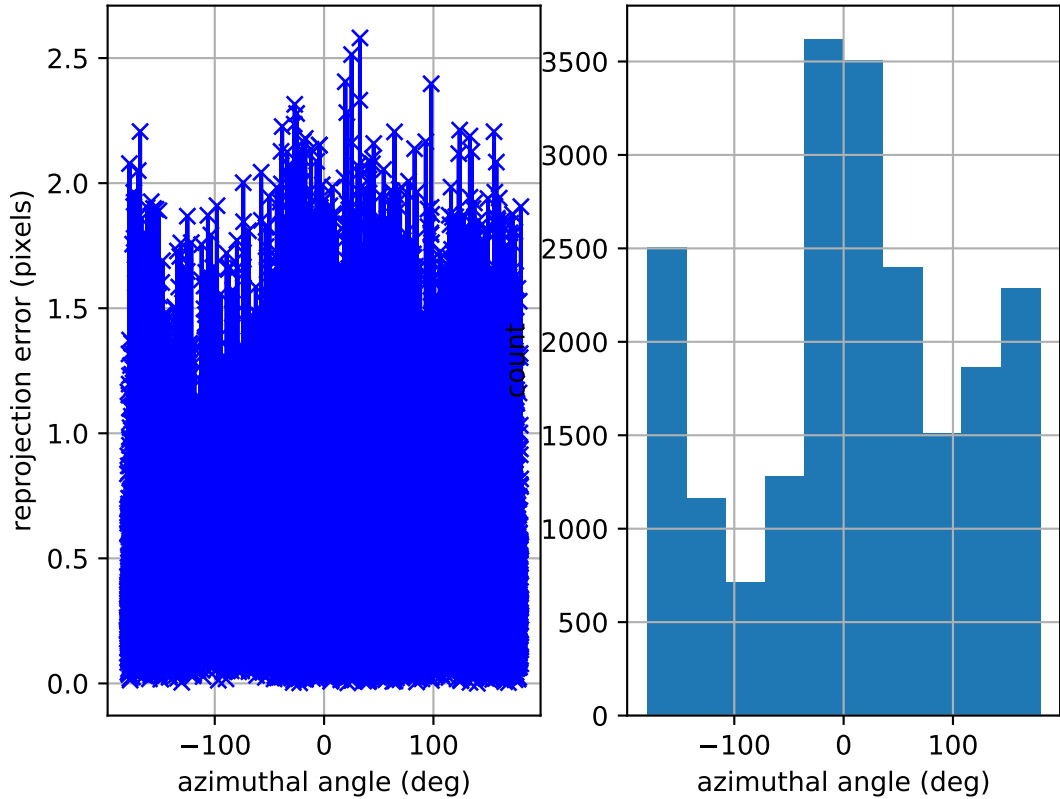
cam1: reprojection errors



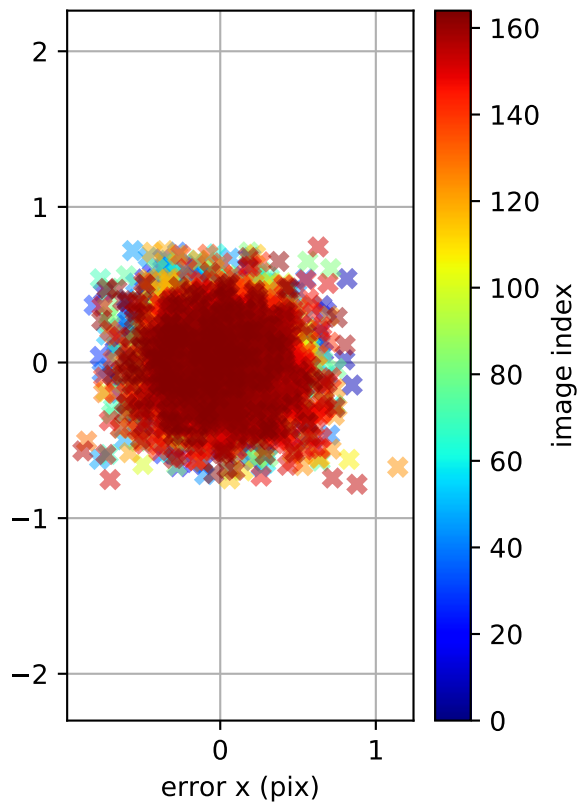
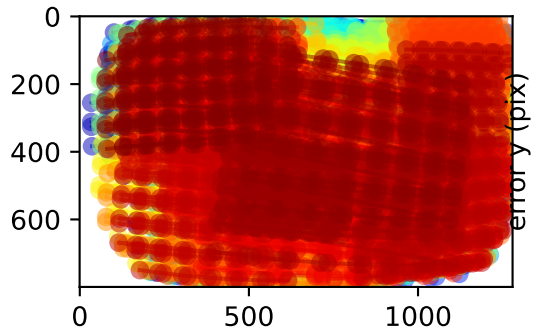
cam2: polar error



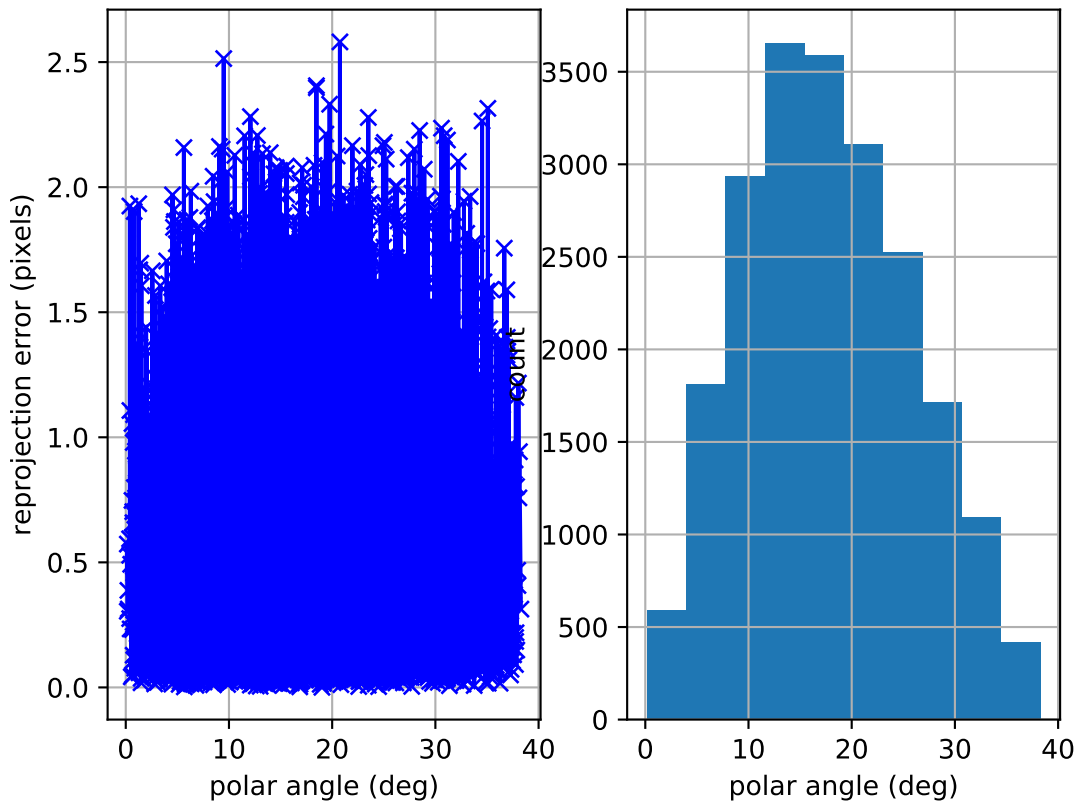
cam2: azimuthal error



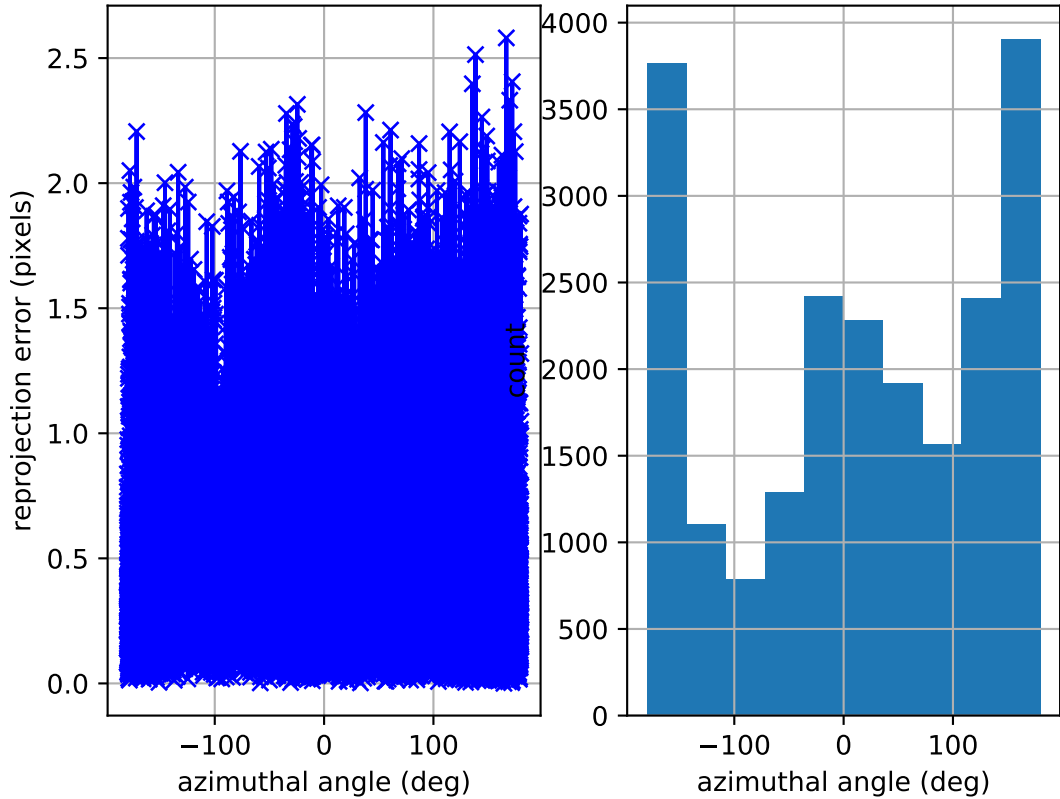
cam2: reprojection errors



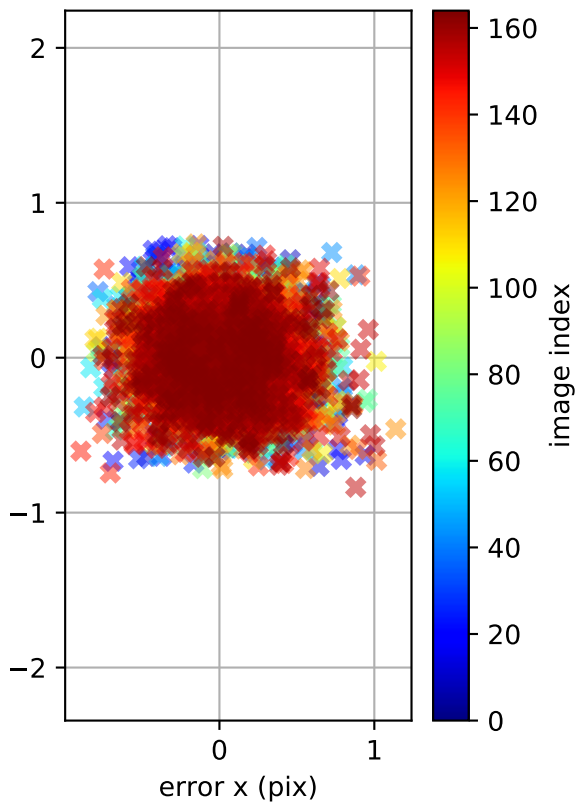
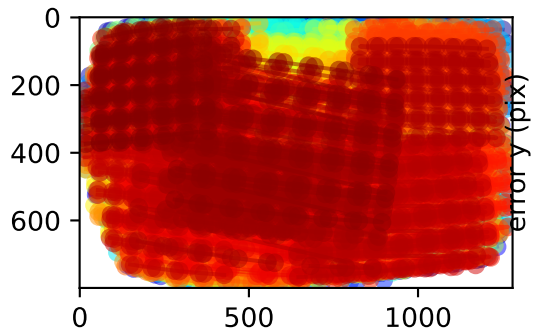
cam3: polar error



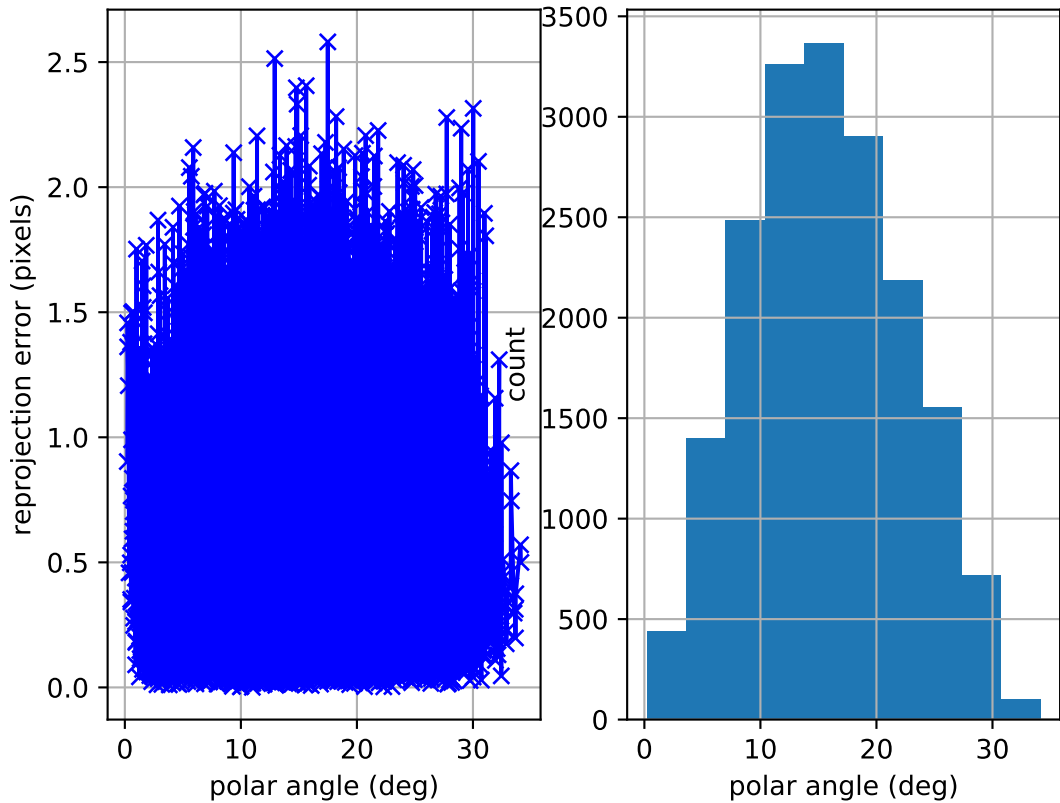
cam3: azimuthal error



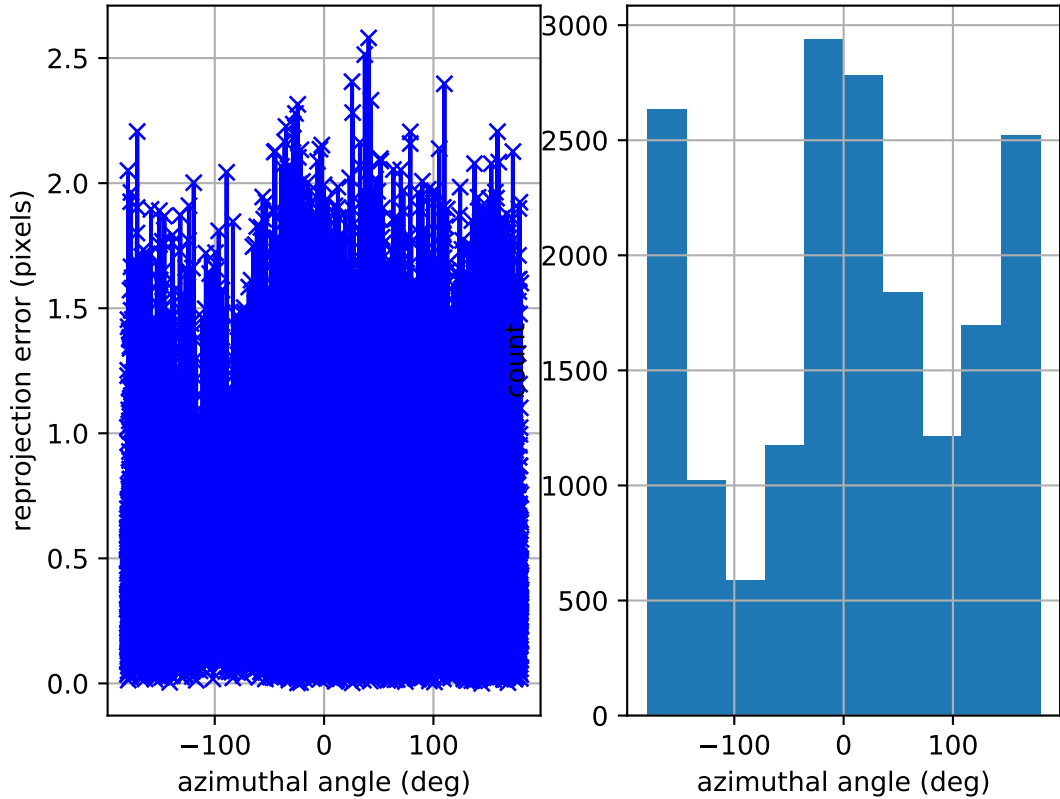
cam3: reprojection errors



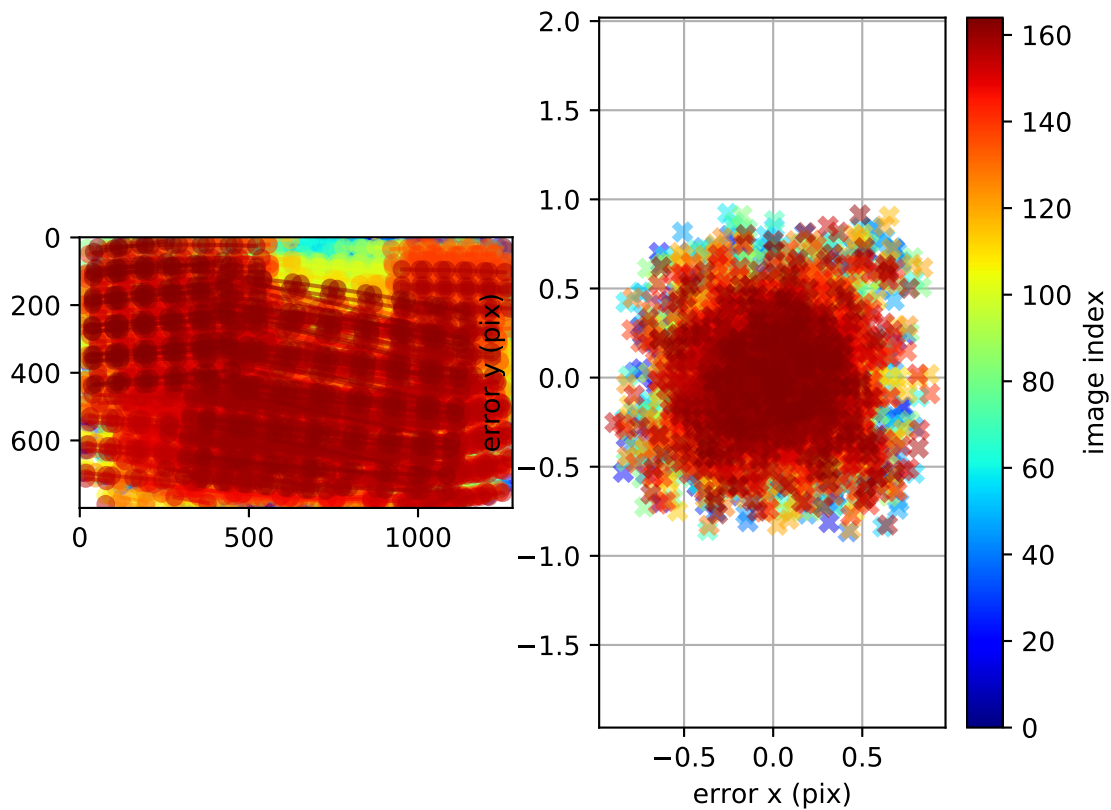
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

