

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.0477465 0.08092581 0.00017181 -0.00098288] +- [0.00106047 0.00242389 0.00008304 0.00005441]
projection: [1032.42244264 1031.73367538 634.3332533 361.48503159] +- [0.13320456 0.13872407 0.00662268 0.12524466]

reprojection error: [0.000086, -0.000009] +- [0.450206, 0.404349]

cam1 (/prophesee/right/events):

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

distortion: [-0.05454919 0.08672544 0.00125919 0.00005505] +- [0.00108325 0.00250312 0.00007962 0.00005333]
projection: [1032.07945225 1031.79034034 635.84470787 364.40775356] +- [0.14666527 0.14945434 0.00399013 0.10024204]

reprojection error: [0.000150, -0.000034] +- [0.481626, 0.446984]

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

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

distortion: [-0.39642062 0.1617453 0.00025797 0.00055138] +- [0.00054444 0.00098546 0.00005883 0.00003482]
projection: [1058.5137246 1058.22678962 674.07306095 334.91462394] +- [0.11434146 0.11769677 0.00492142 0.24271918]

reprojection error: [0.000232, -0.000113] +- [0.180147, 0.161935]

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

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

distortion: [-0.39570448 0.15834695 0.00014842 0.00103219] +- [0.00048387 0.0007973 0.00005271 0.00003364]
projection: [1053.21688643 1053.2758901 672.73933711 327.08741436] +- [0.11762217 0.12022845 0.00550027 0.23576582]

reprojection error: [0.000211, -0.000137] +- [0.193346, 0.159760]

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

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

distortion: [-0.41887837 0.19475166 0.00052888 -0.00010095] +- [0.00083321 0.00216506 0.00005818 0.00003842]
projection: [1265.03812043 1264.38739423 653.51662644 365.03777541] +- [0.12228796 0.12252706 0.00343135 0.08468846]

reprojection error: [0.000117, 0.000013] +- [0.176798, 0.158699]

baseline T_1_0:

q: [-0.00053457 0.00216884 -0.00028481 0.99999746] +- [0.00008663 0.00004989 0.00004342]

t: [-0.12016726 0.00096875 -0.00001222] +- [0.00003068 0.00003042 0.00011135]

baseline T_2_1:

q: [0.00000124 -0.0039341 -0.00478967 0.99998079] +- [0.00027804 0.00004812 0.00004014]

t: [0.1202754 0.06918197 0.0035827] +- [0.00002822 0.00002768 0.00010372]

baseline T_3_2:

q: [0.00000279 0.00081104 0.00031937 0.99999962] +- [0.00033851 0.00004128 0.0000353]

t: [-0.1200108 -0.00012394 0.00048819] +- [0.00002517 0.00002361 0.00009406]

baseline T_4_3:

q: [0.00234009 0.002023 0.0003216 0.99999516] +- [0.00026553 0.00003952 0.00003459]

t: [0.08885609 0.00620683 0.00302945] +- [0.00002431 0.0000218 0.00008876]

Target configuration

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Type: aprilgrid

Tags:

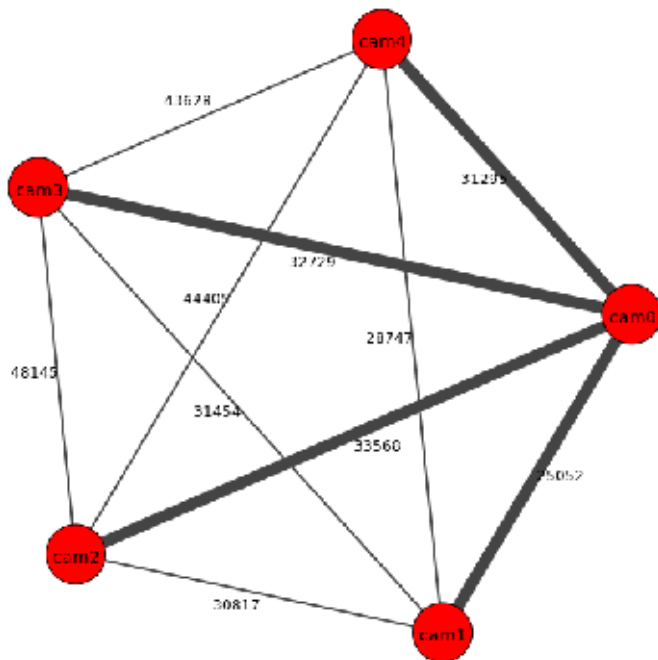
Rows: 5

Cols: 7

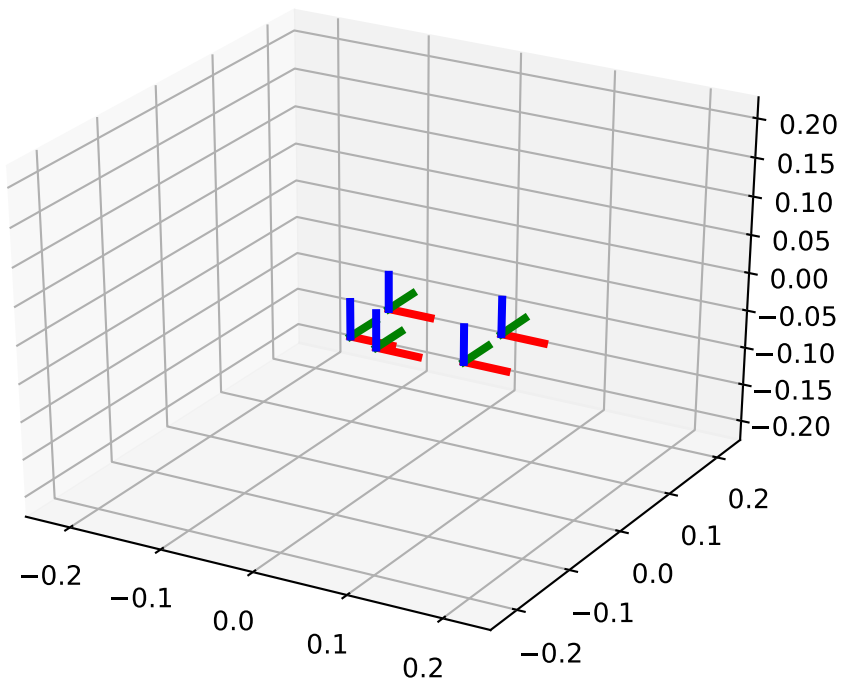
Size: 0.04 [m]

Spacing 0.01 [m]

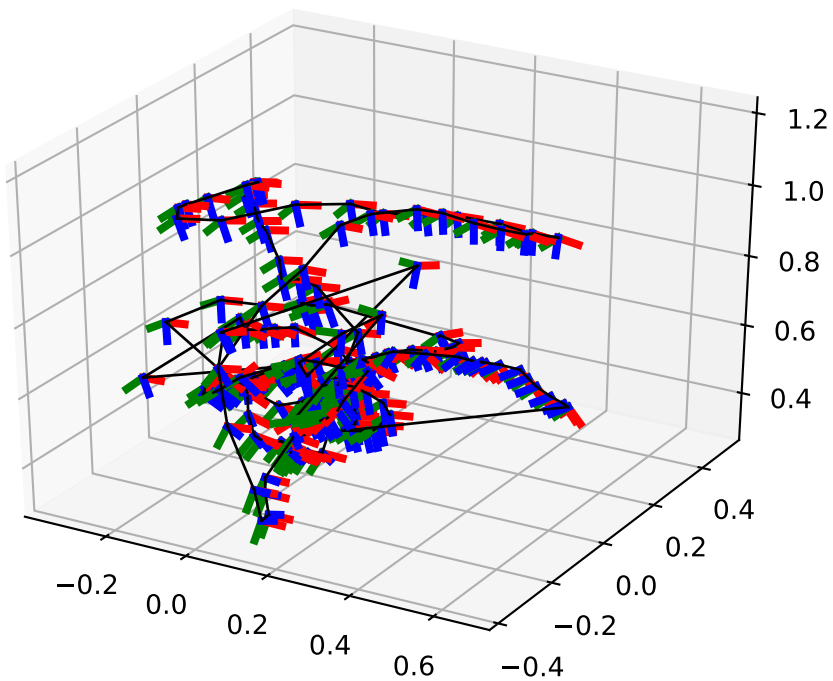
Inter-camera observations graph (edge weight=#mutual obs.)



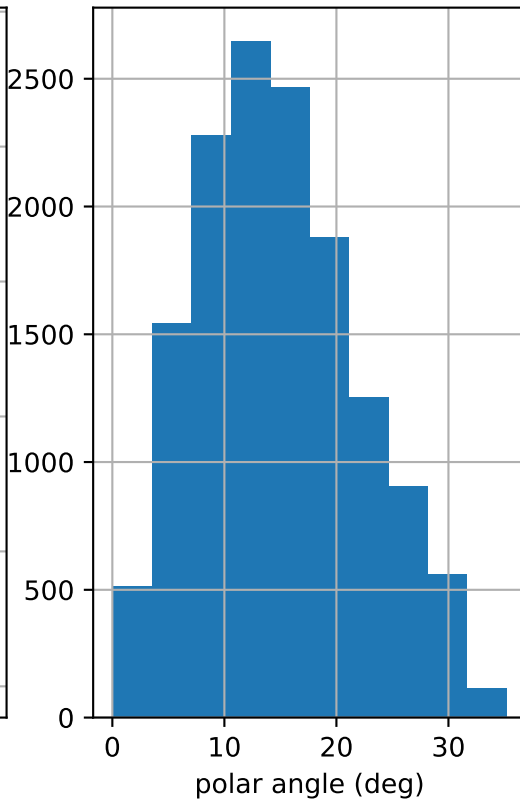
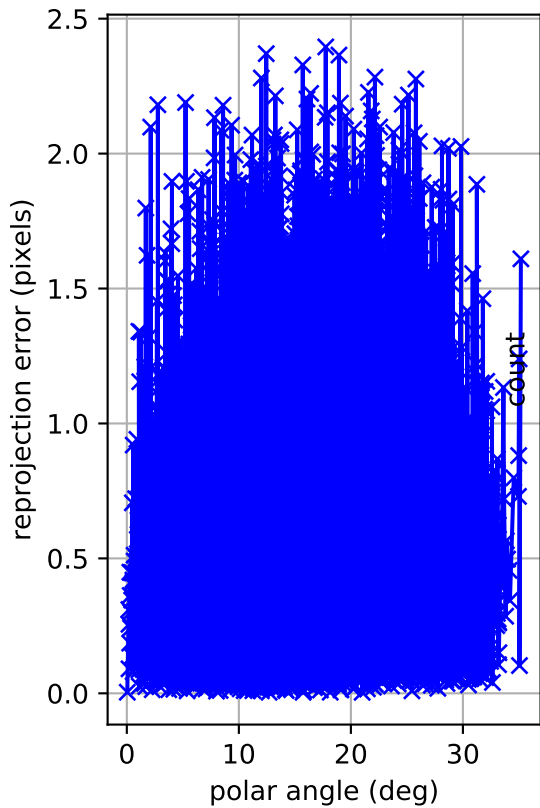
camera system



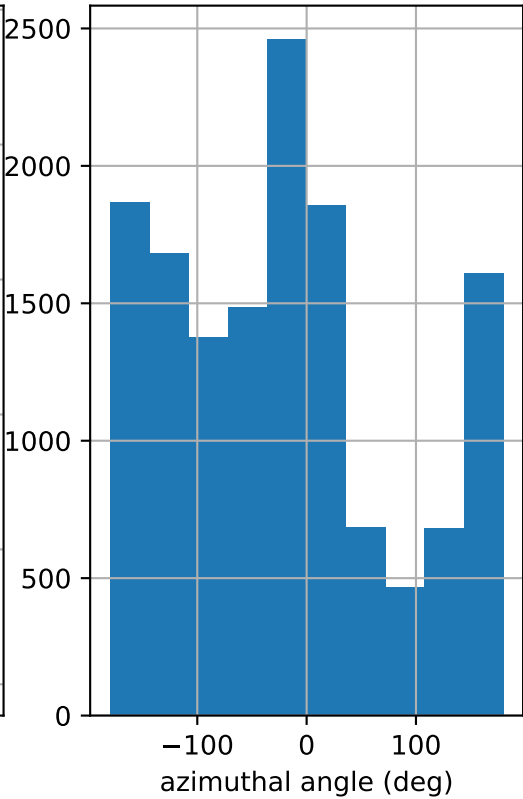
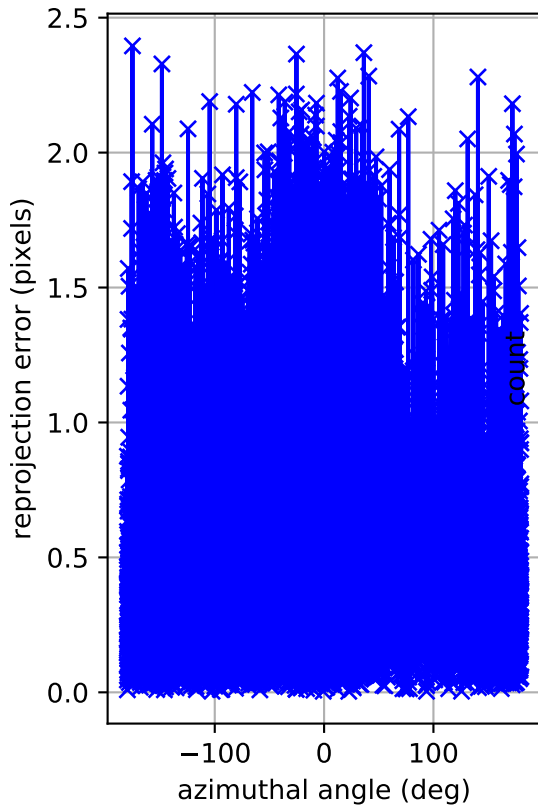
cam0: estimated poses



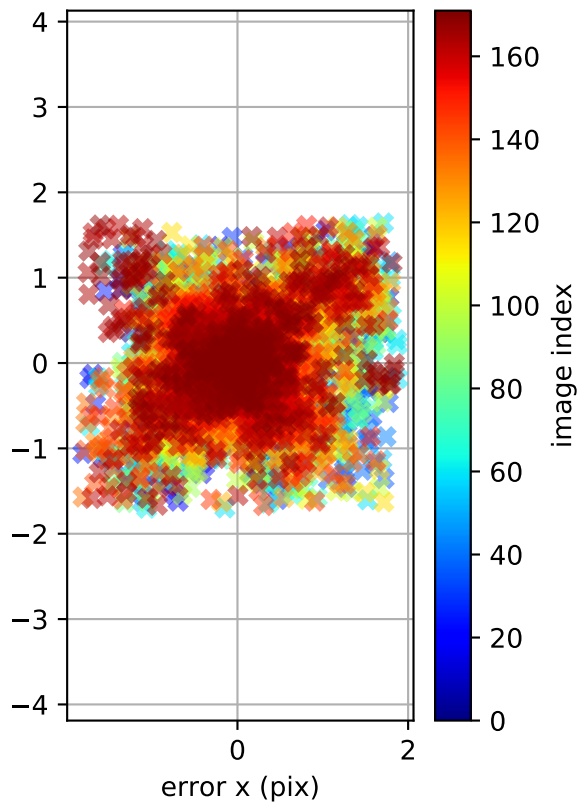
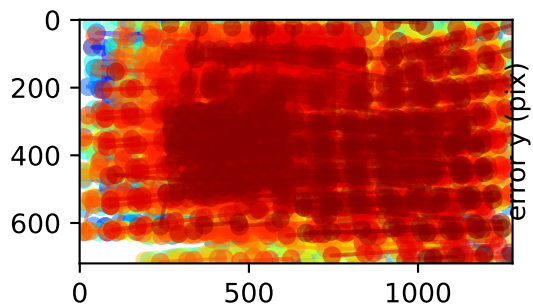
cam0: polar error



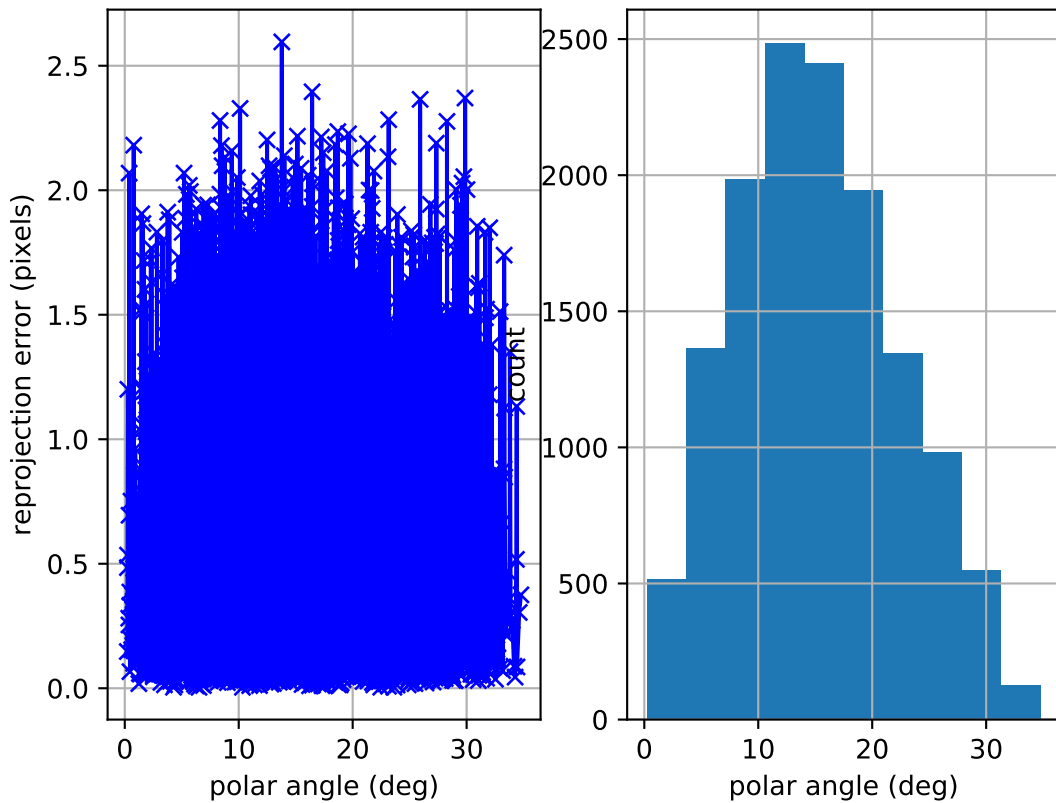
cam0: azimuthal error



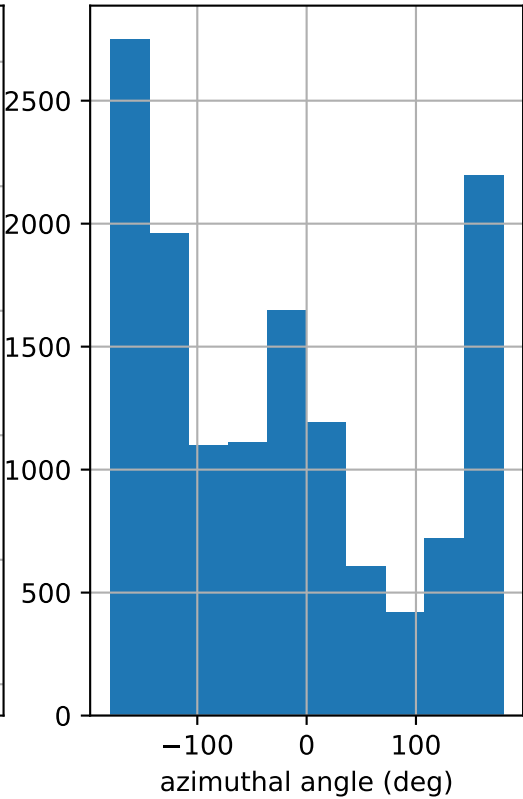
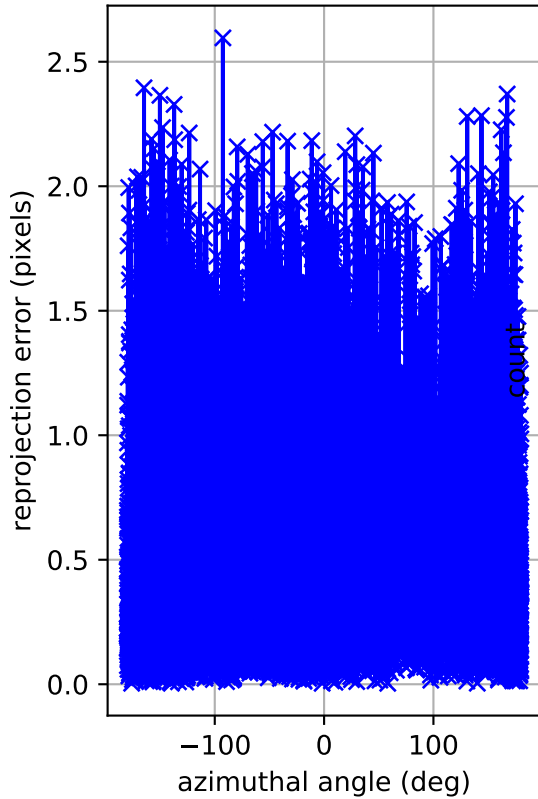
cam0: reprojection errors



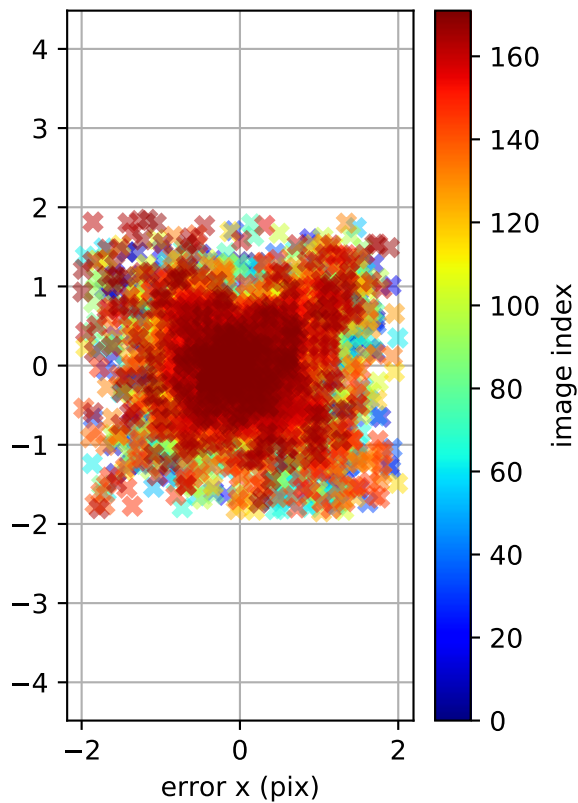
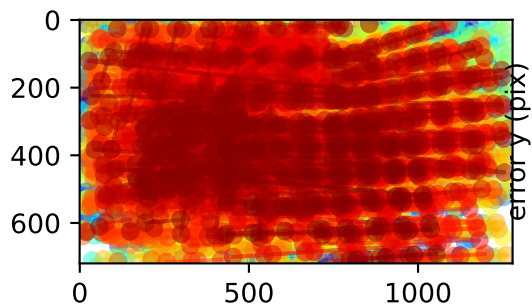
cam1: polar error



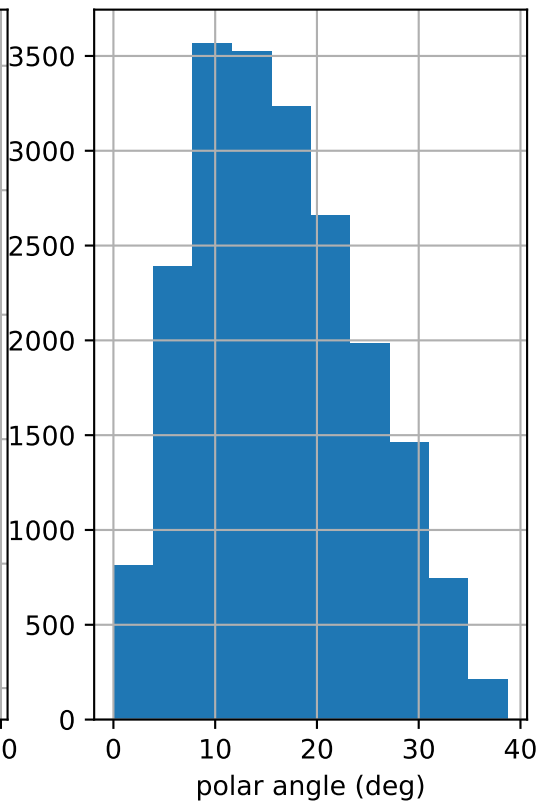
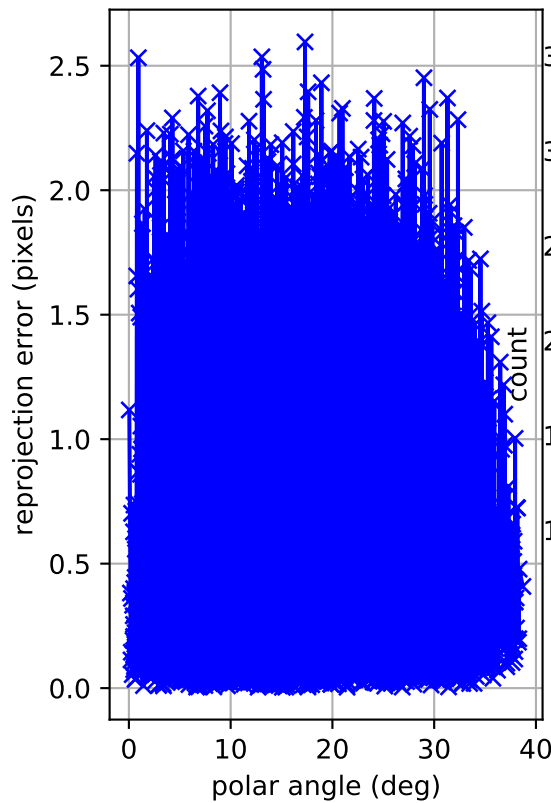
cam1: azimuthal error



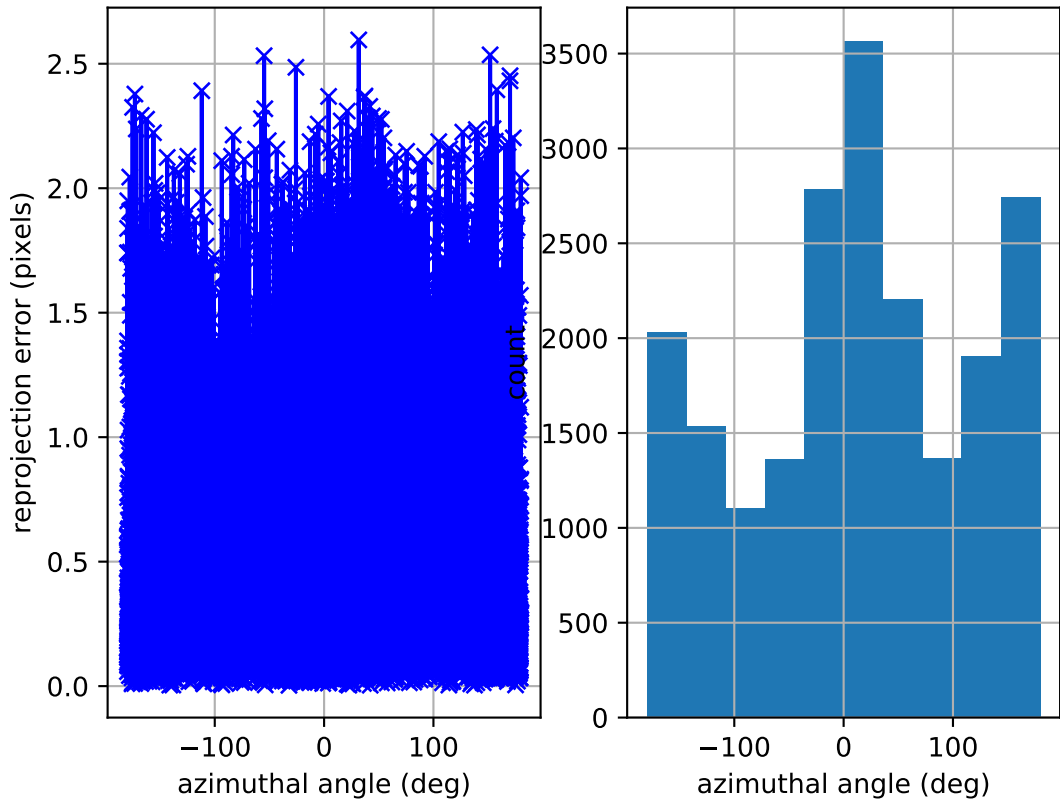
cam1: reprojection errors



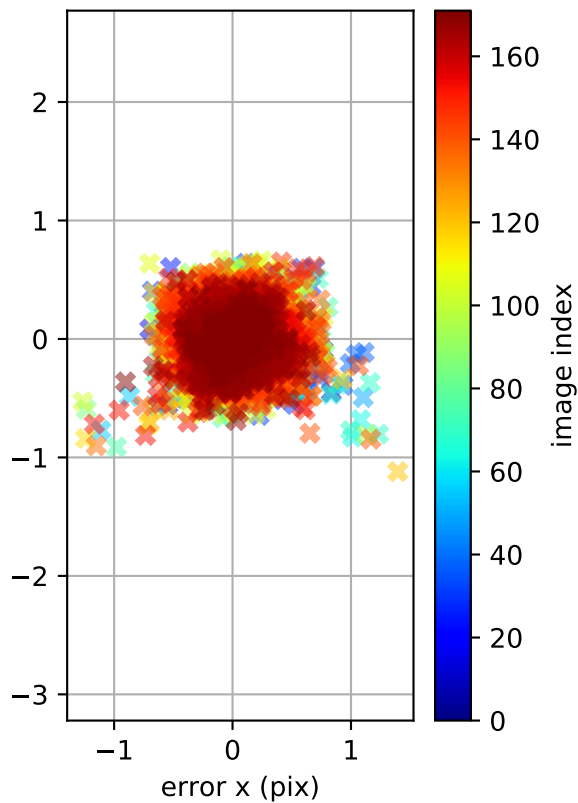
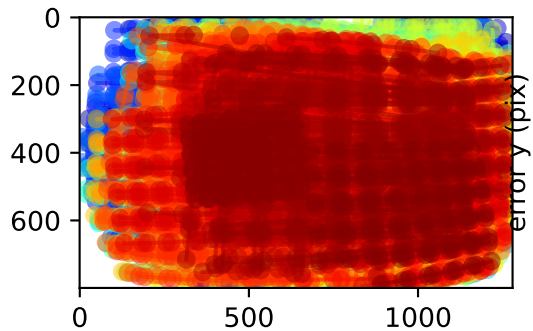
cam2: polar error



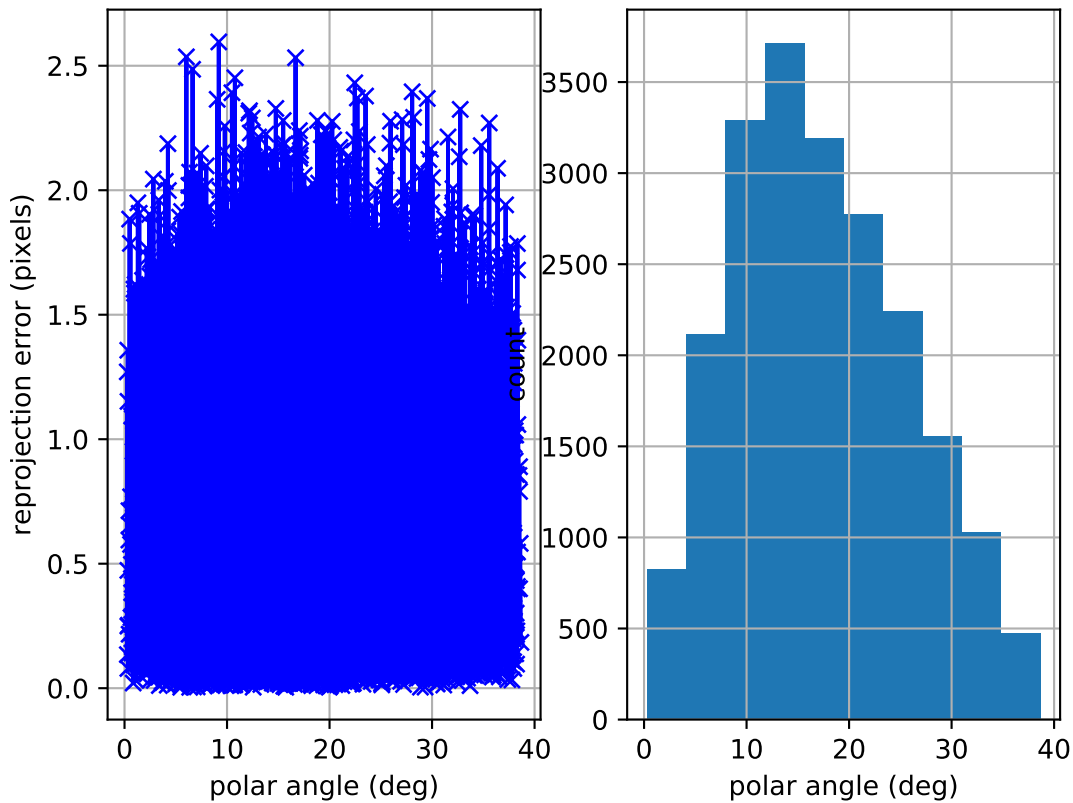
cam2: azimuthal error



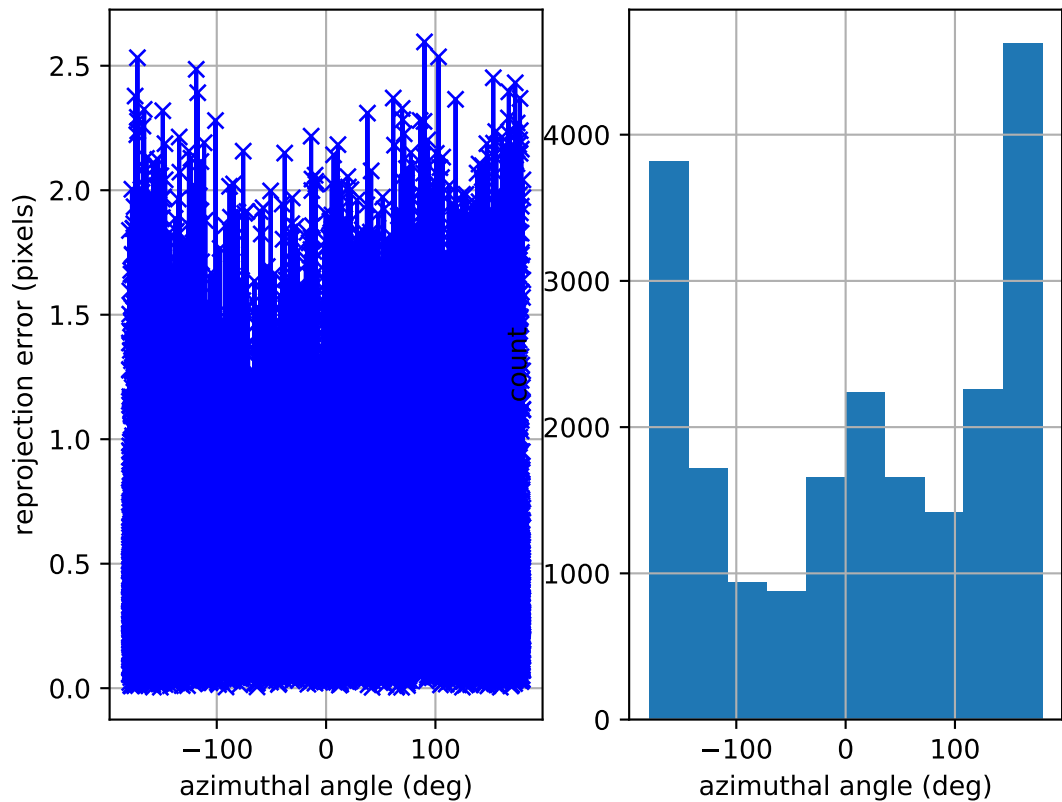
cam2: reprojection errors



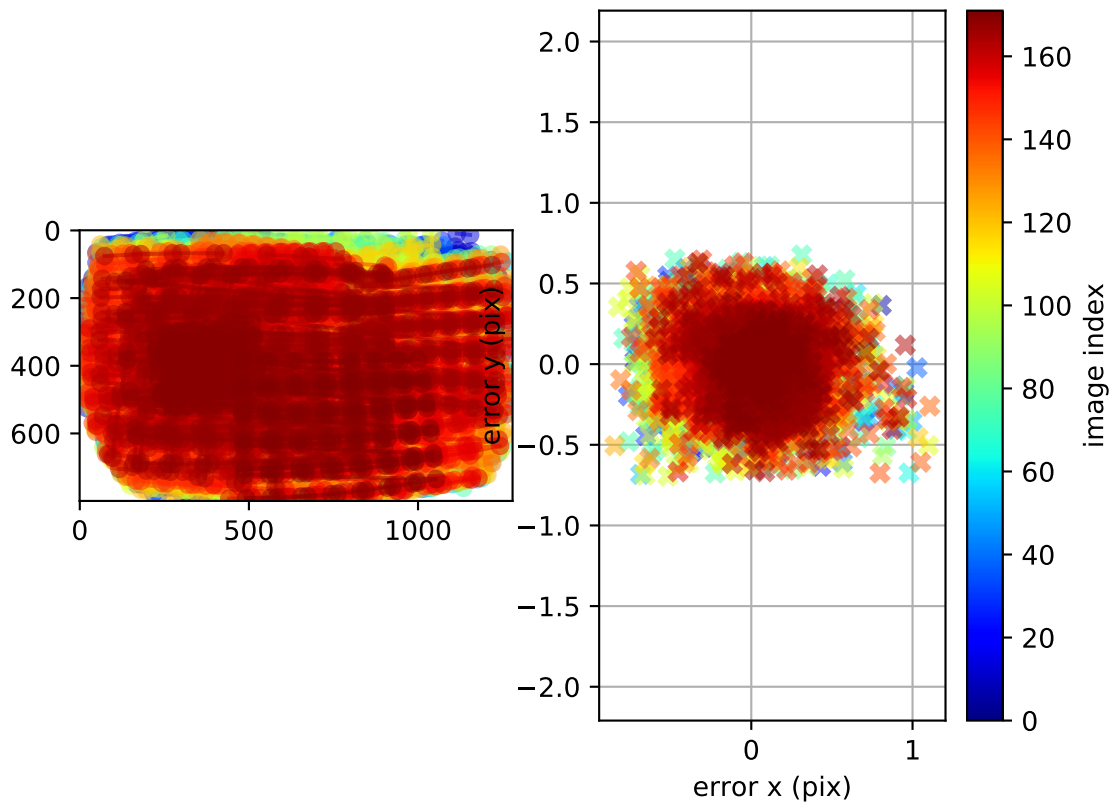
cam3: polar error



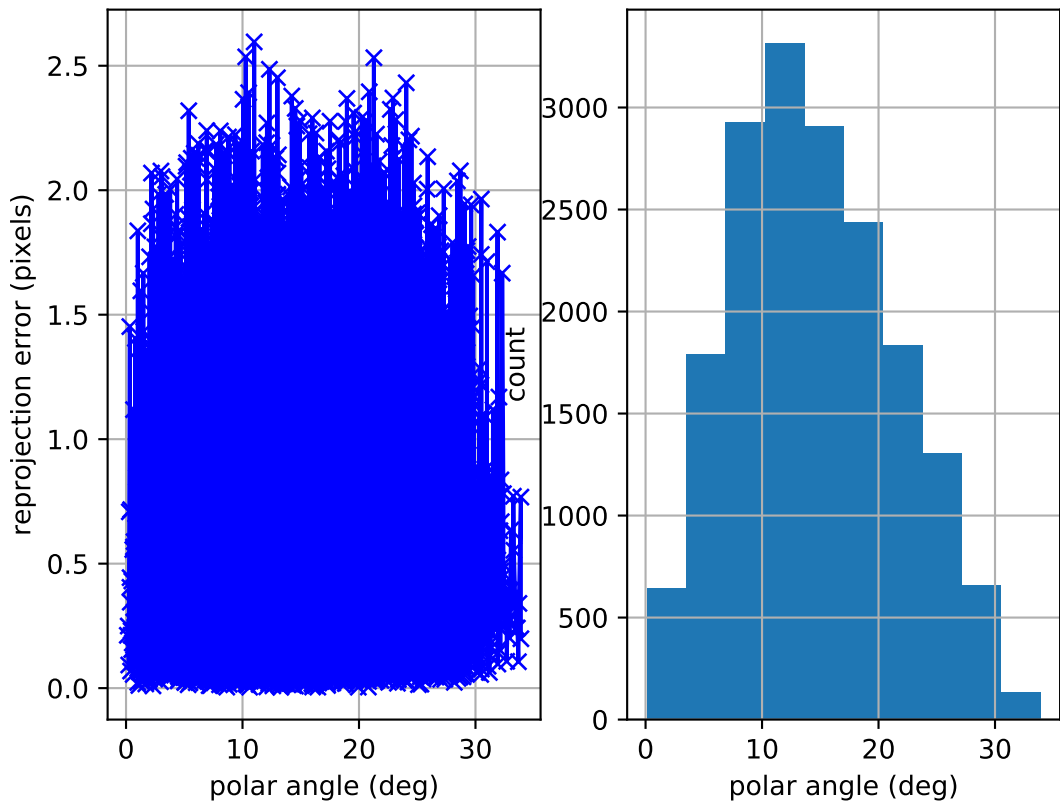
cam3: azimuthal error



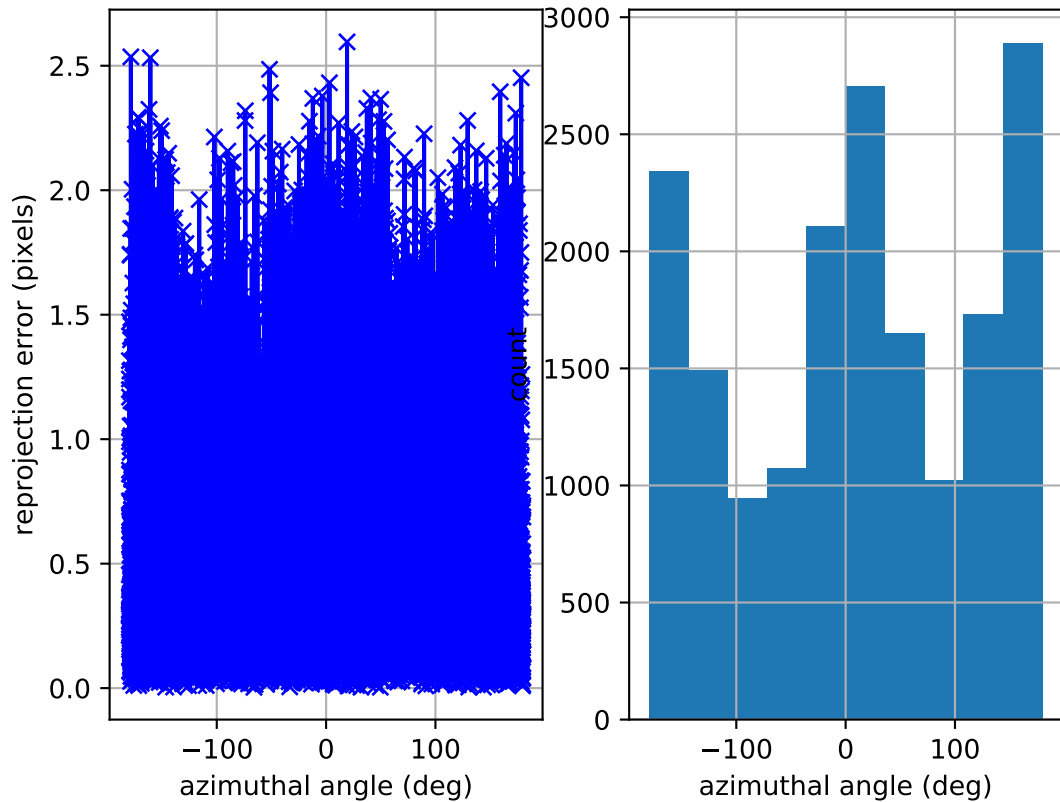
cam3: reprojection errors



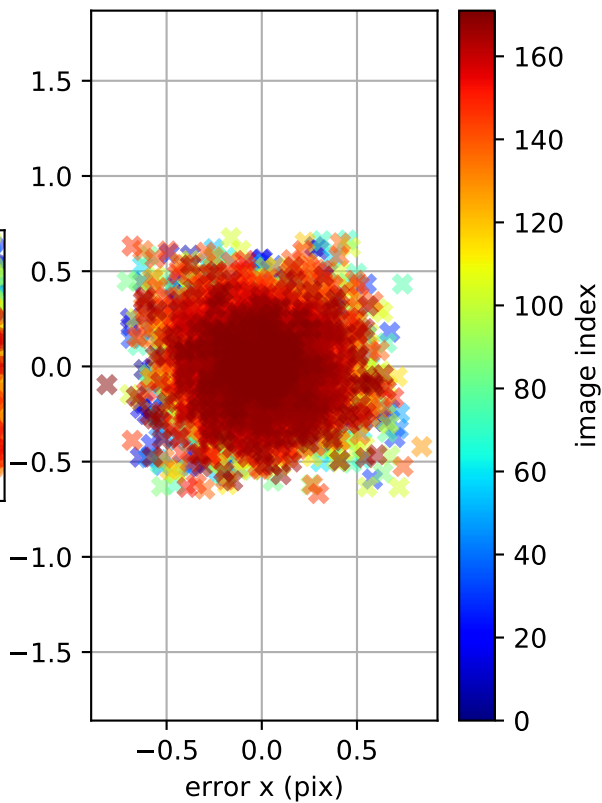
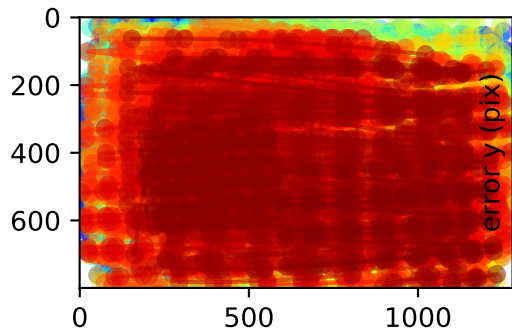
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

