

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.05093798 0.08881425 -0.00061596 -0.00133413] +- [0.00101299 0.00229162 0.00009237 0.00005926]
projection: [1030.50264615 1029.70020336 635.01492542 358.49225262] +- [0.11849262 0.13354615 0.00675033 0.19421728]

reprojection error: [0.000280, 0.000019] +- [0.424092, 0.355516]

cam1 (/prophesee/right/events):

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

distortion: [-0.05550998 0.08660342 0.00062759 0.00034794] +- [0.0010344 0.00227095 0.00008574 0.00006937]
projection: [1030.60407107 1030.17429737 636.95552131 362.92223123] +- [0.12472672 0.13539835 0.00730196 0.04092161]

reprojection error: [0.000219, 0.000042] +- [0.411873, 0.356836]

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

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

distortion: [-0.39976472 0.17241433 0.00043147 -0.0000574] +- [0.00063139 0.0012749 0.00006772 0.00004046]
projection: [1055.9230872 1055.79362068 676.71192483 332.66151396] +- [0.10748206 0.11873706 0.01725242 0.22256437]

reprojection error: [0.000182, 0.000068] +- [0.184751, 0.153219]

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

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

distortion: [-0.39582656 0.15832577 0.00027703 0.00033518] +- [0.00050569 0.00079727 0.0000642 0.00004784]
projection: [1051.22572485 1051.3014088 675.67446067 325.22390443] +- [0.10944619 0.11547402 0.00711053 0.23025097]

reprojection error: [0.000113, 0.000041] +- [0.218055, 0.161412]

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

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

distortion: [-0.41859088 0.1959396 0.00060155 -0.0007538] +- [0.0008534 0.00229637 0.00006383 0.0000435]
projection: [1261.90678372 1261.29627325 656.93308497 363.98400118] +- [0.11159687 0.11999288 0.00408551 0.06120933]

reprojection error: [-0.000076, 0.000051] +- [0.194567, 0.171182]

baseline T_1_0:

q: [-0.00060525 0.00324796 -0.00018621 0.99999452] +- [0.0001769 0.00003911 0.00004315]

t: [-0.12024293 0.00095027 -0.00002534] +- [0.00002517 0.00002556 0.00009133]

baseline T_2_1:

q: [-0.0002624 -0.00428659 -0.00482535 0.99997914] +- [0.0002187 0.00004048 0.00004131]

t: [0.12027886 0.06919154 0.00301172] +- [0.00002357 0.00002385 0.00008897]

baseline T_3_2:

q: [-0.00018863 0.0011066 0.00041025 0.99999929] +- [0.00035008 0.00003875 0.00003766]

t: [-0.12011168 -0.00009287 0.00072298] +- [0.00002174 0.00002136 0.00008452]

baseline T_4_3:

q: [0.00189059 0.00196385 0.00028102 0.99999624] +- [0.00024958 0.00003116 0.00003627]

t: [0.08894328 0.00618345 0.00283877] +- [0.0000205 0.00001934 0.00007751]

Target configuration

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Type: aprilgrid

Tags:

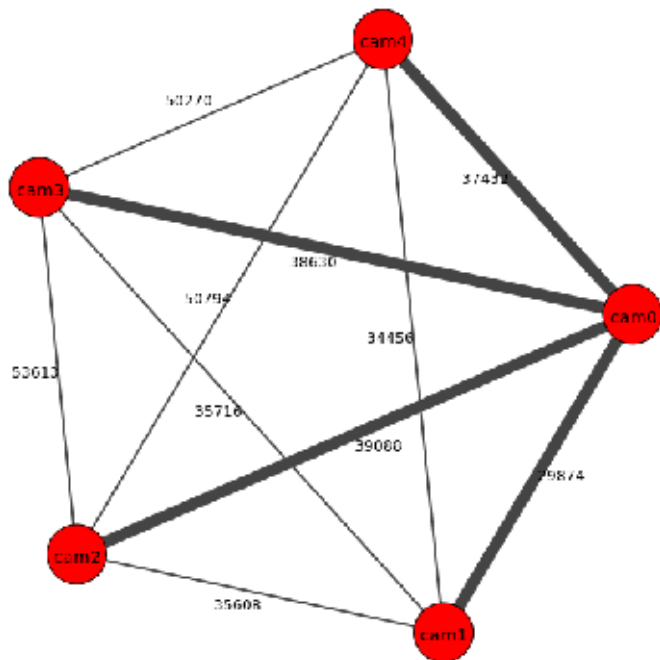
Rows: 5

Cols: 7

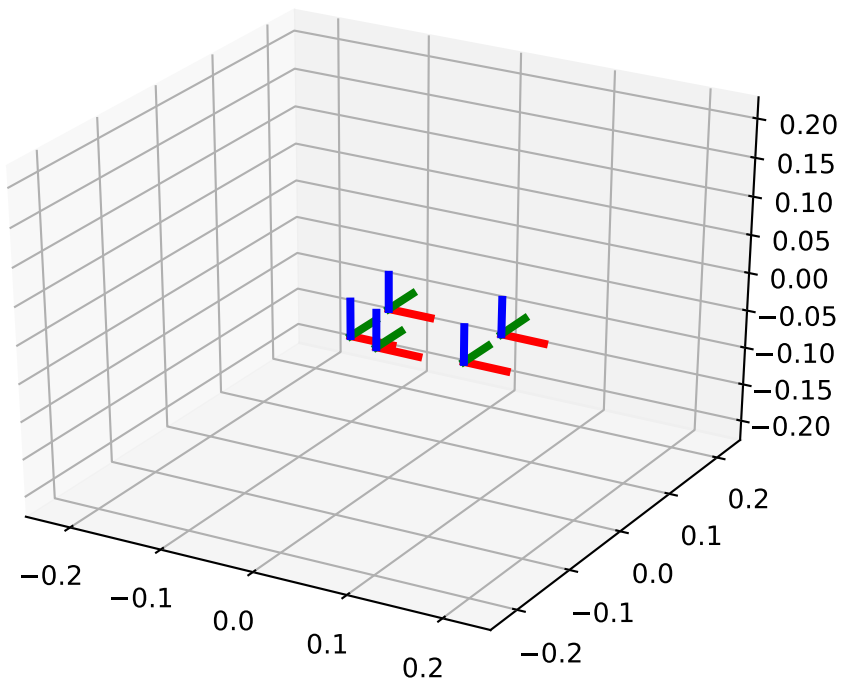
Size: 0.04 [m]

Spacing 0.01 [m]

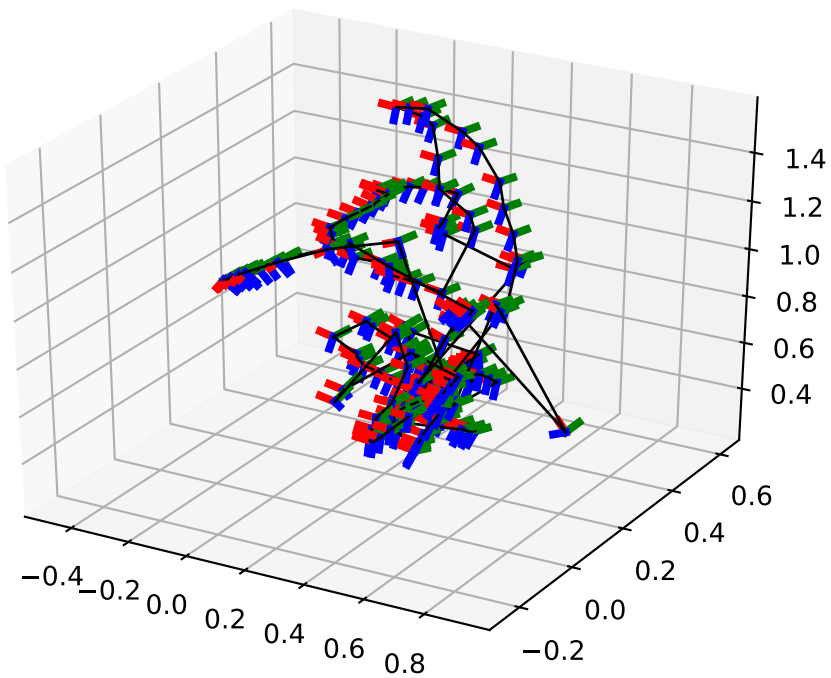
Inter-camera observations graph (edge weight=#mutual obs.)



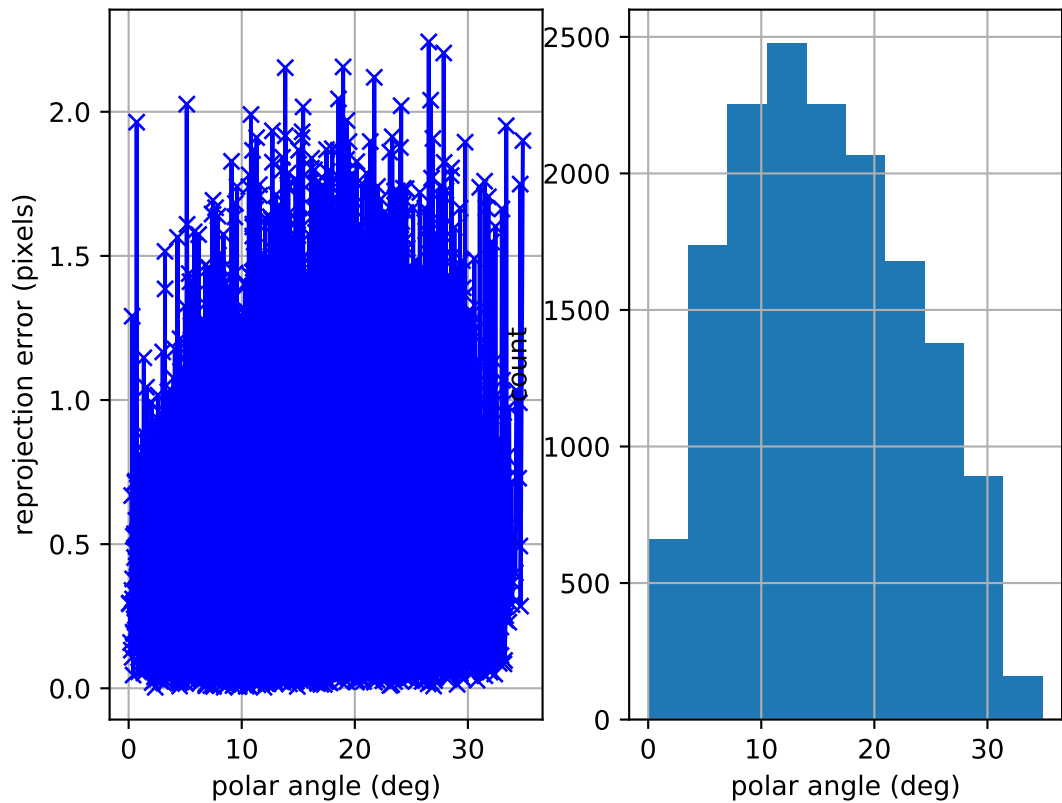
camera system



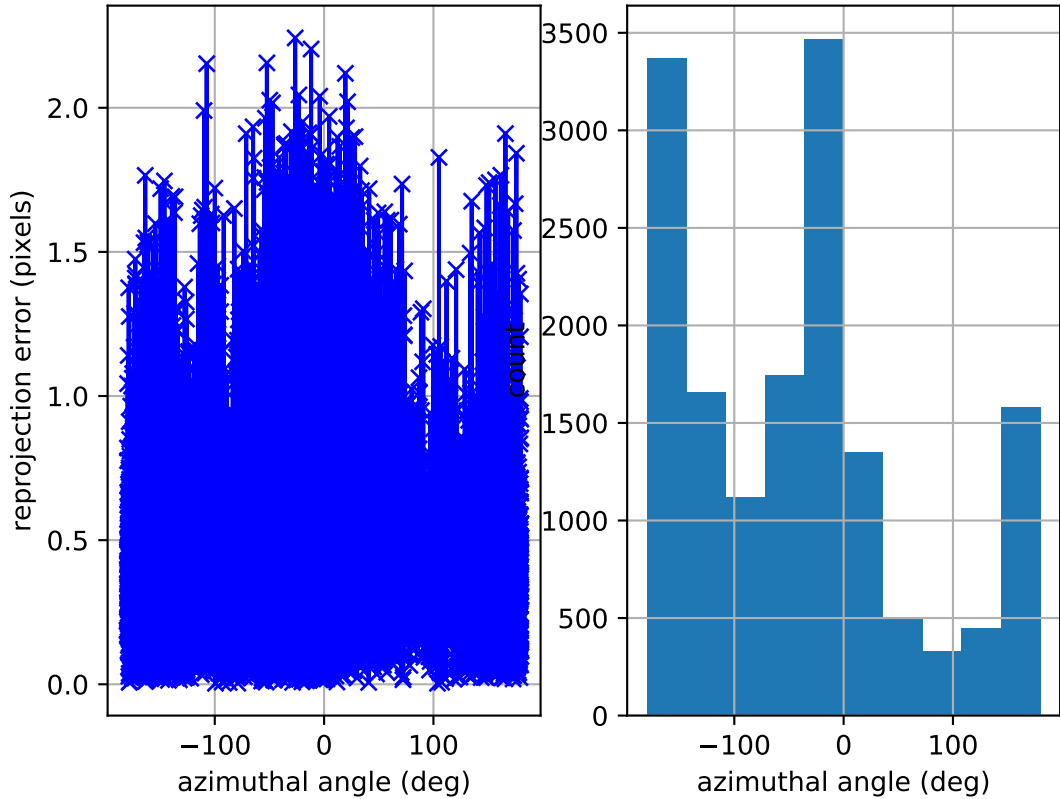
cam0: estimated poses



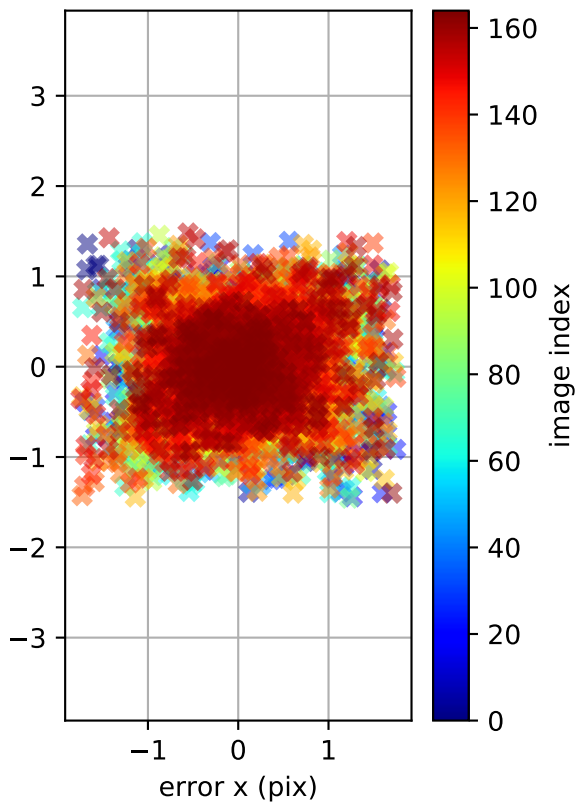
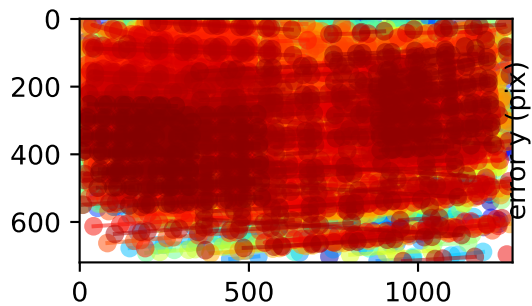
cam0: polar error



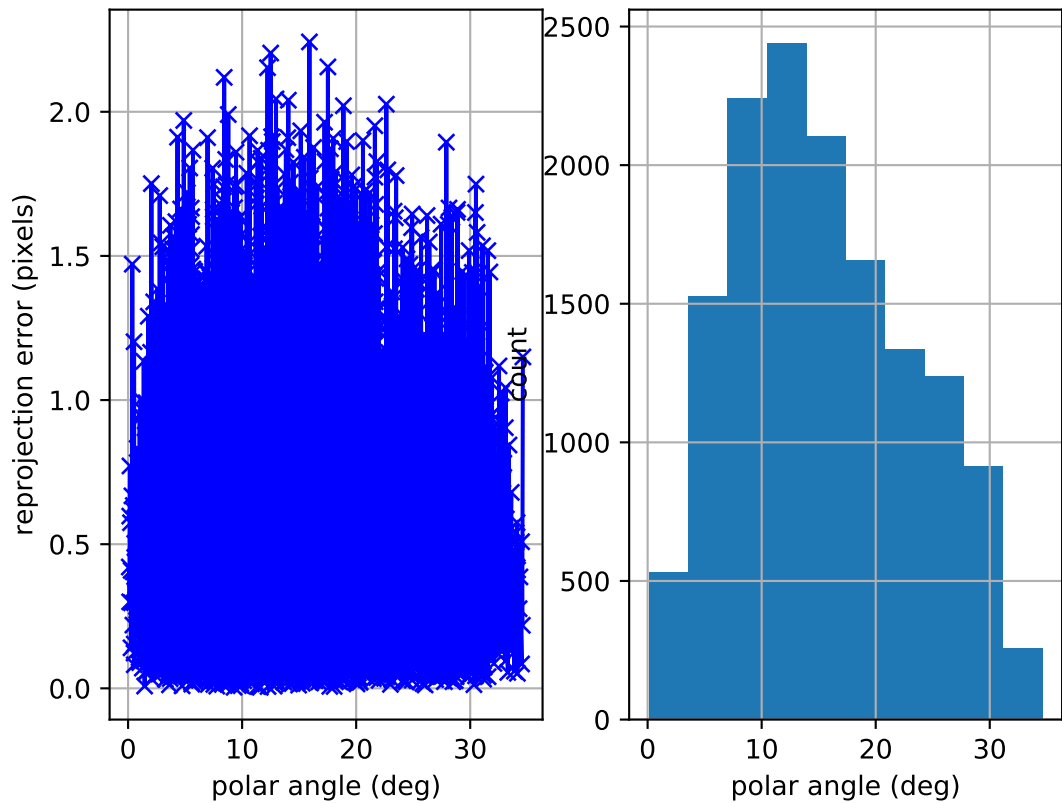
cam0: azimuthal error



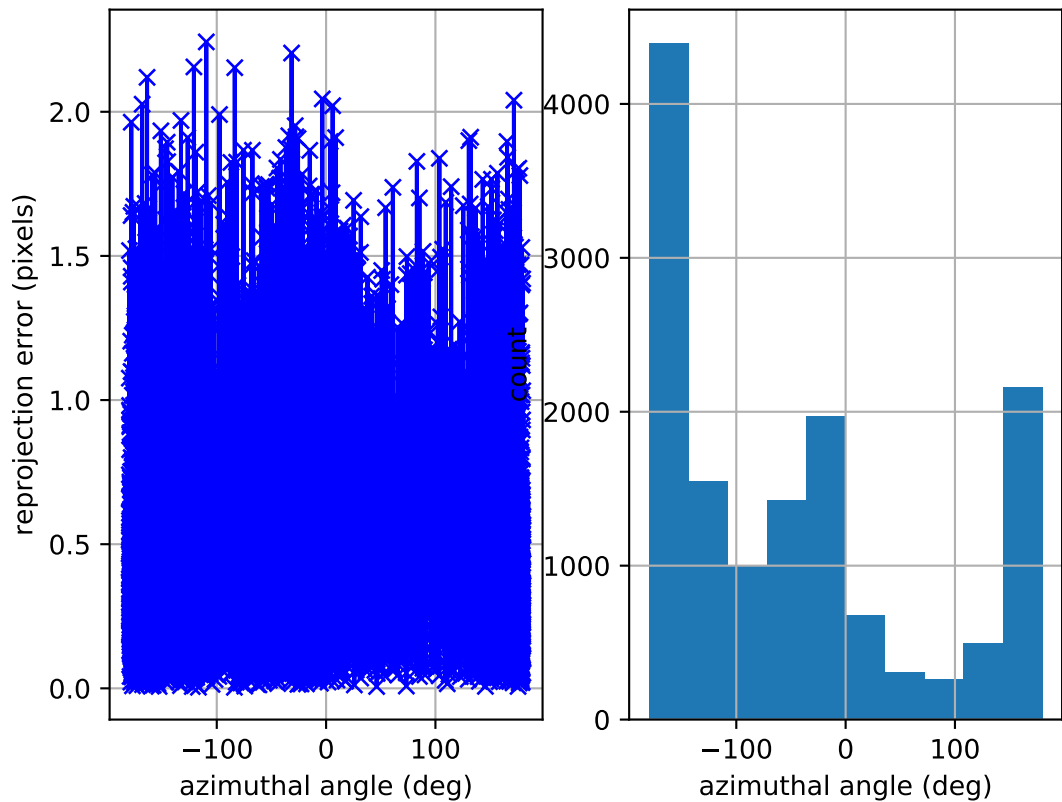
cam0: reprojection errors



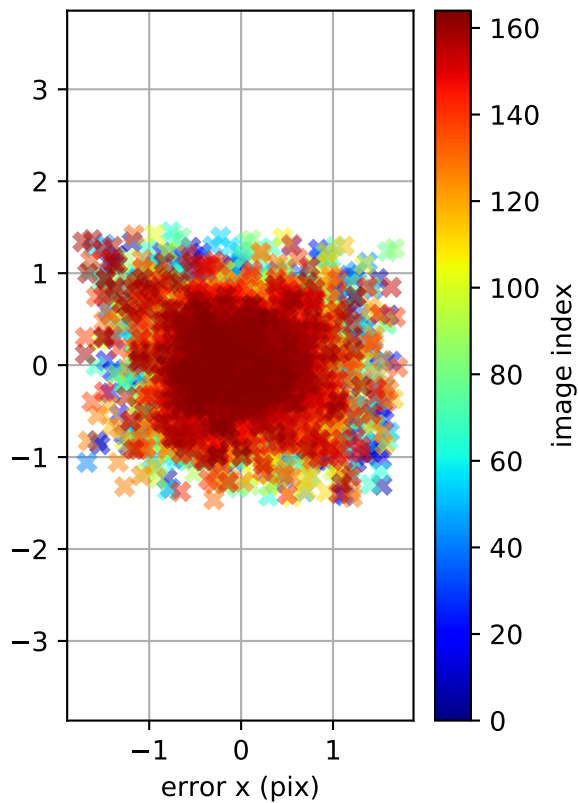
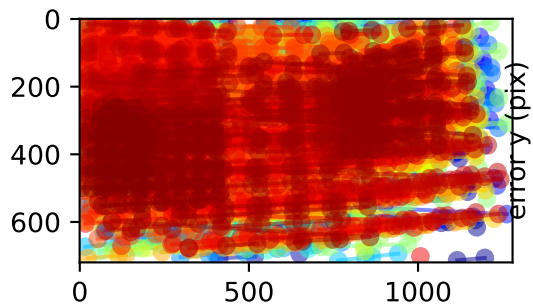
cam1: polar error



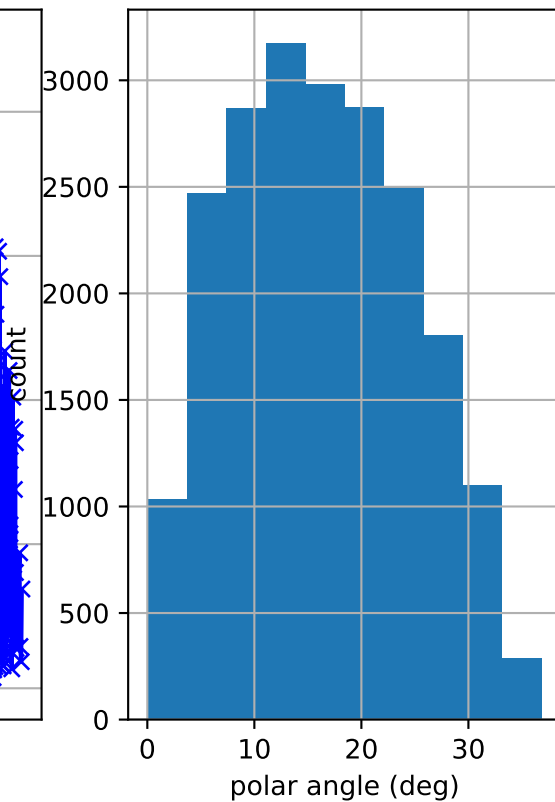
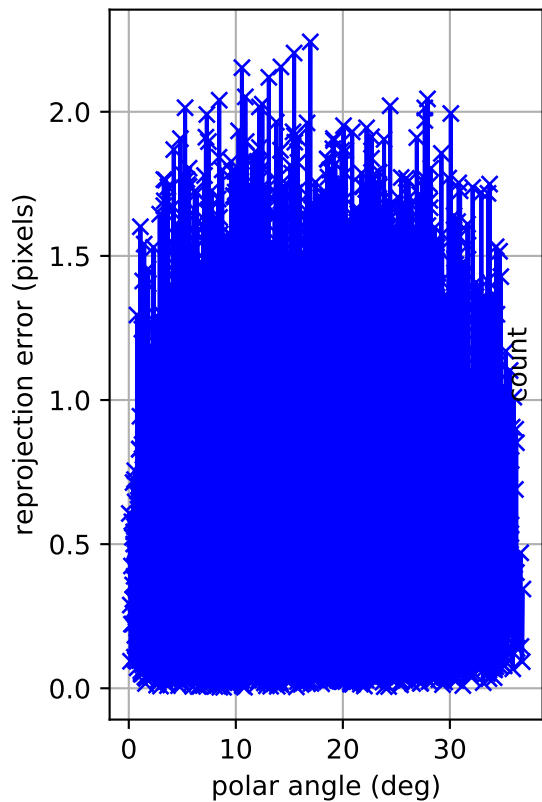
cam1: azimuthal error



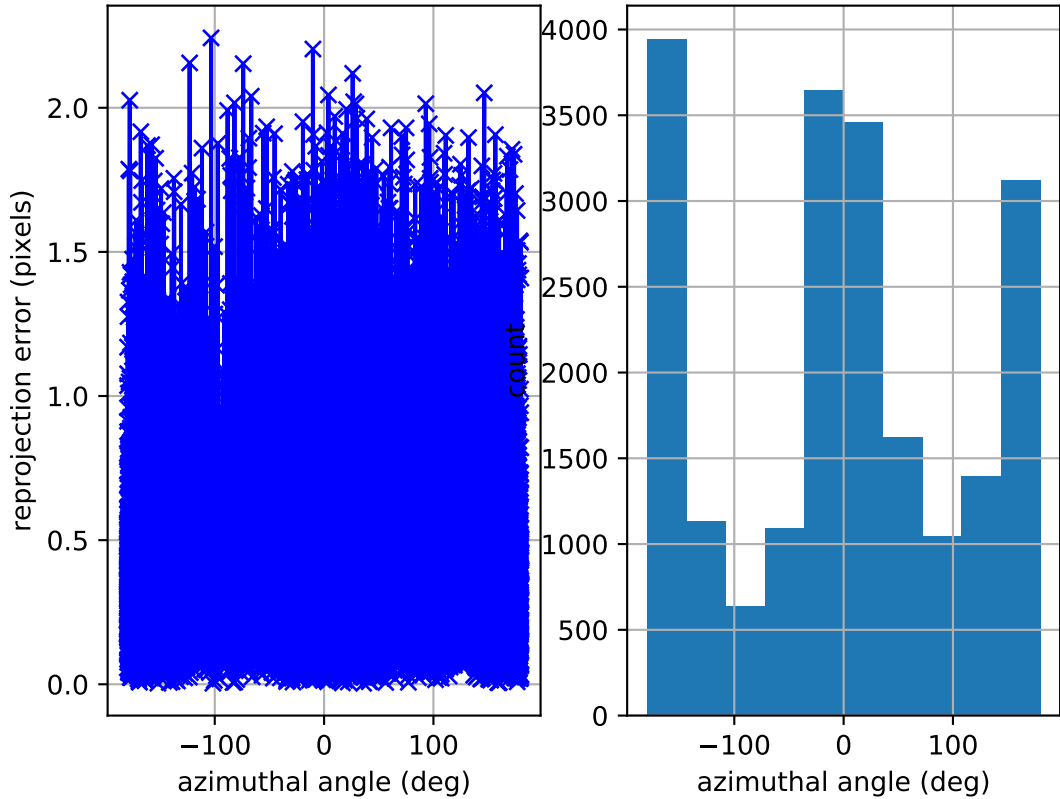
cam1: reprojection errors



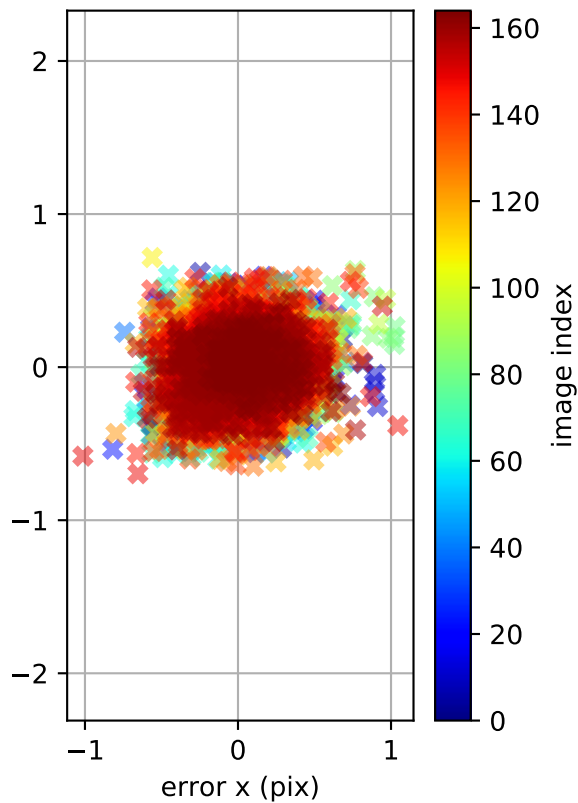
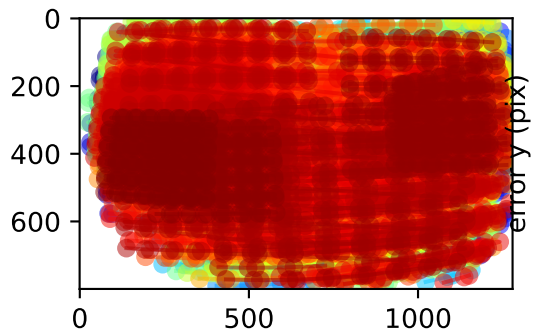
cam2: polar error



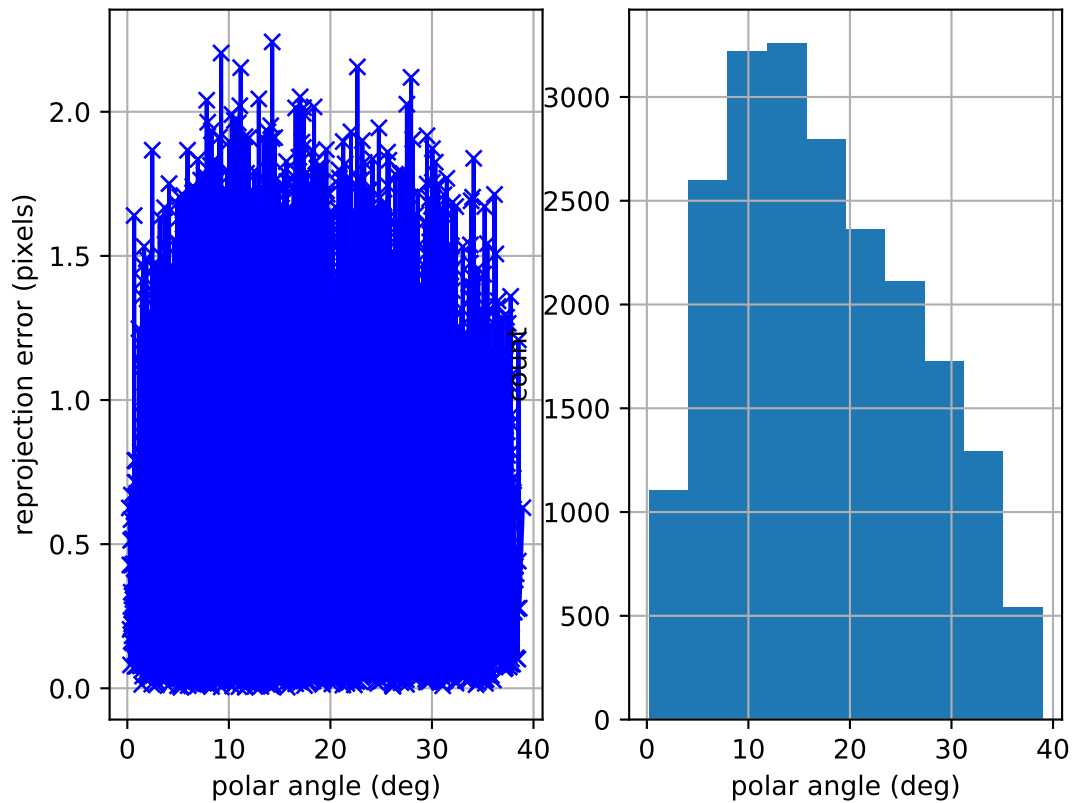
cam2: azimuthal error



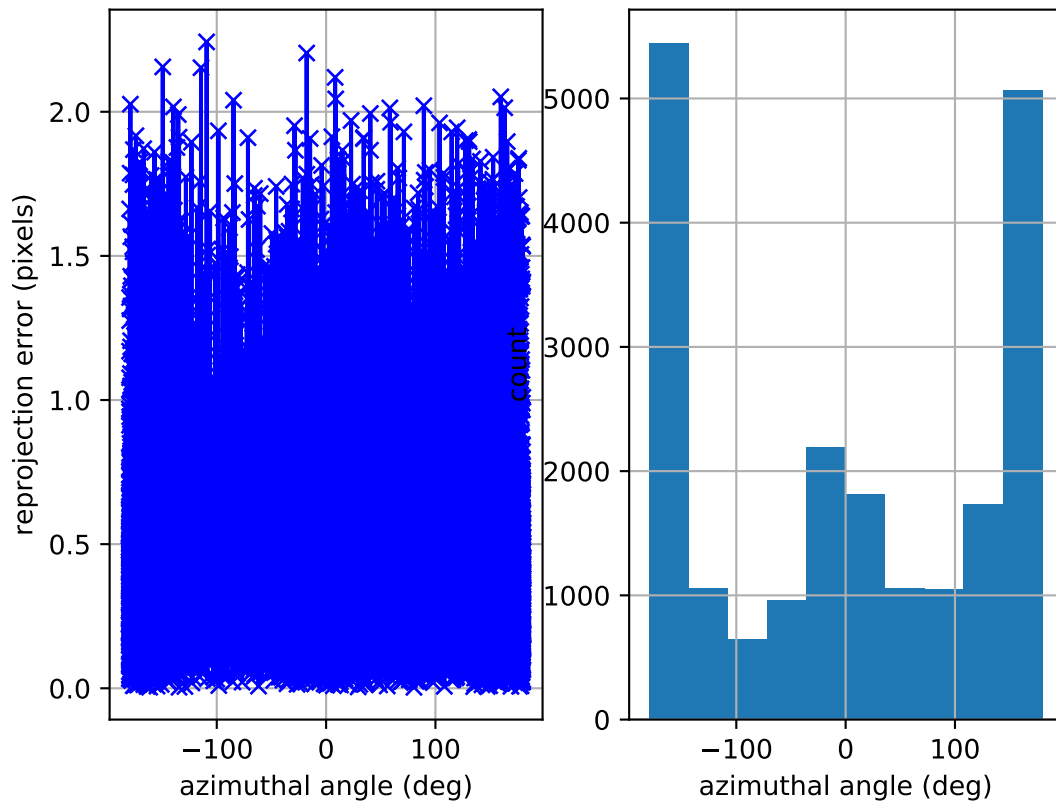
cam2: reprojection errors



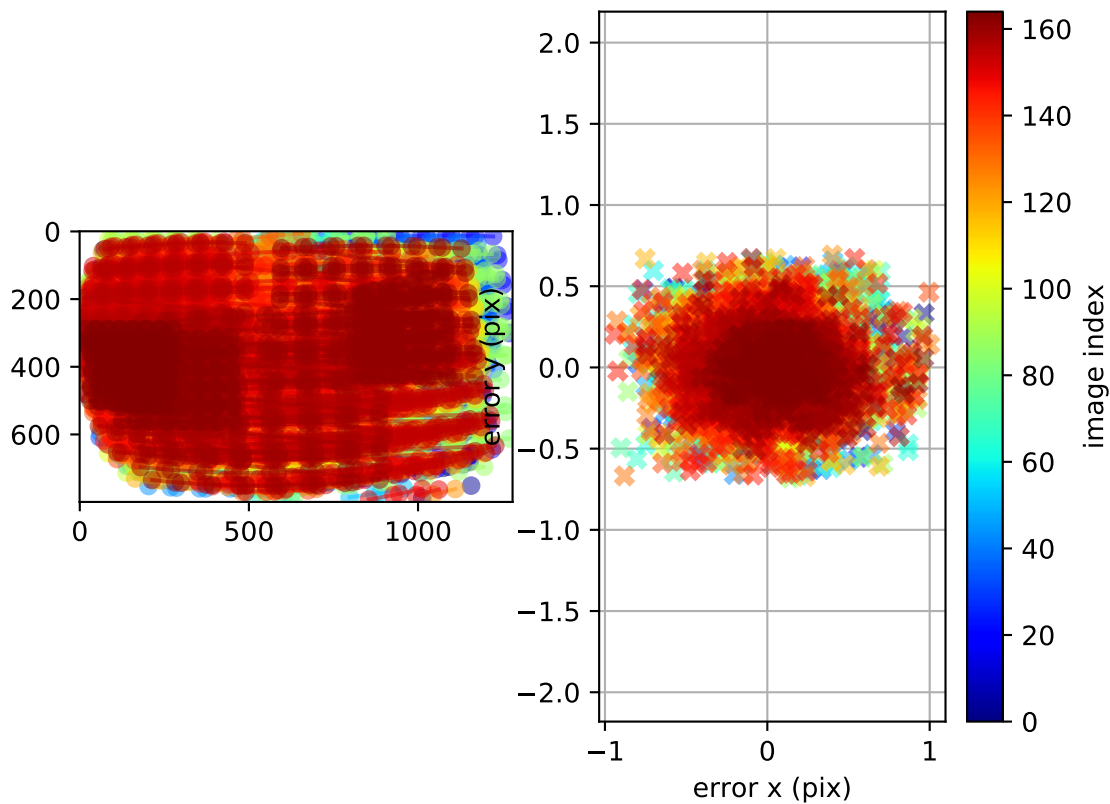
cam3: polar error



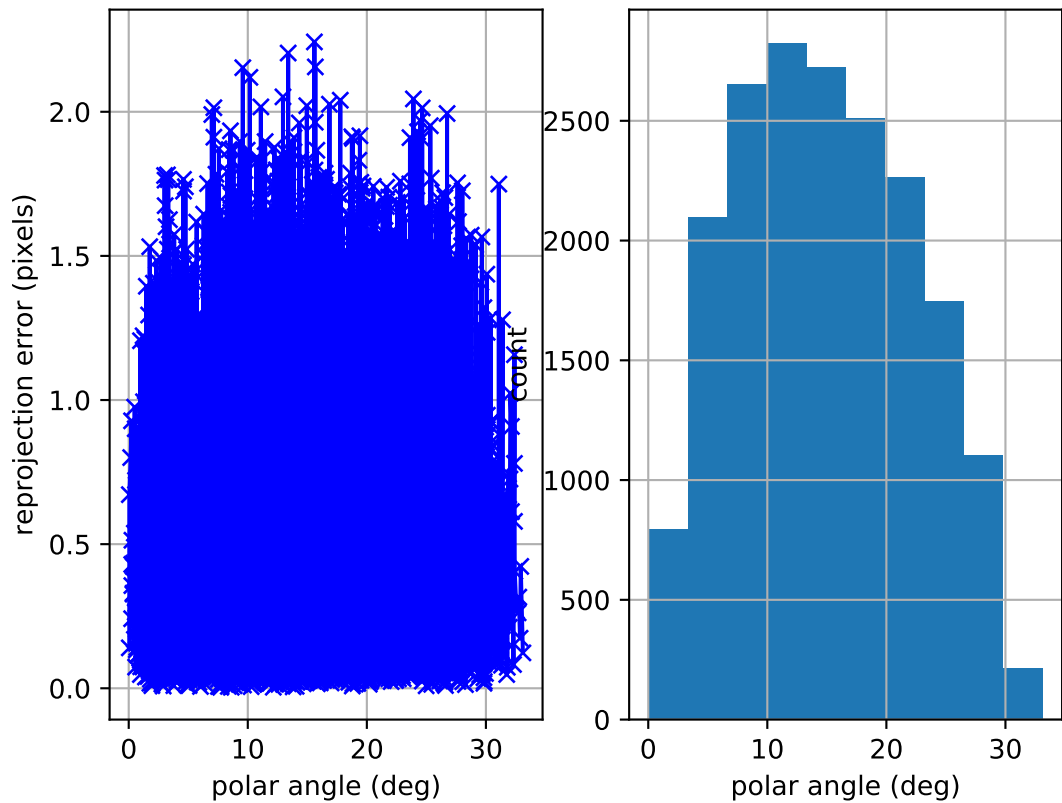
cam3: azimuthal error



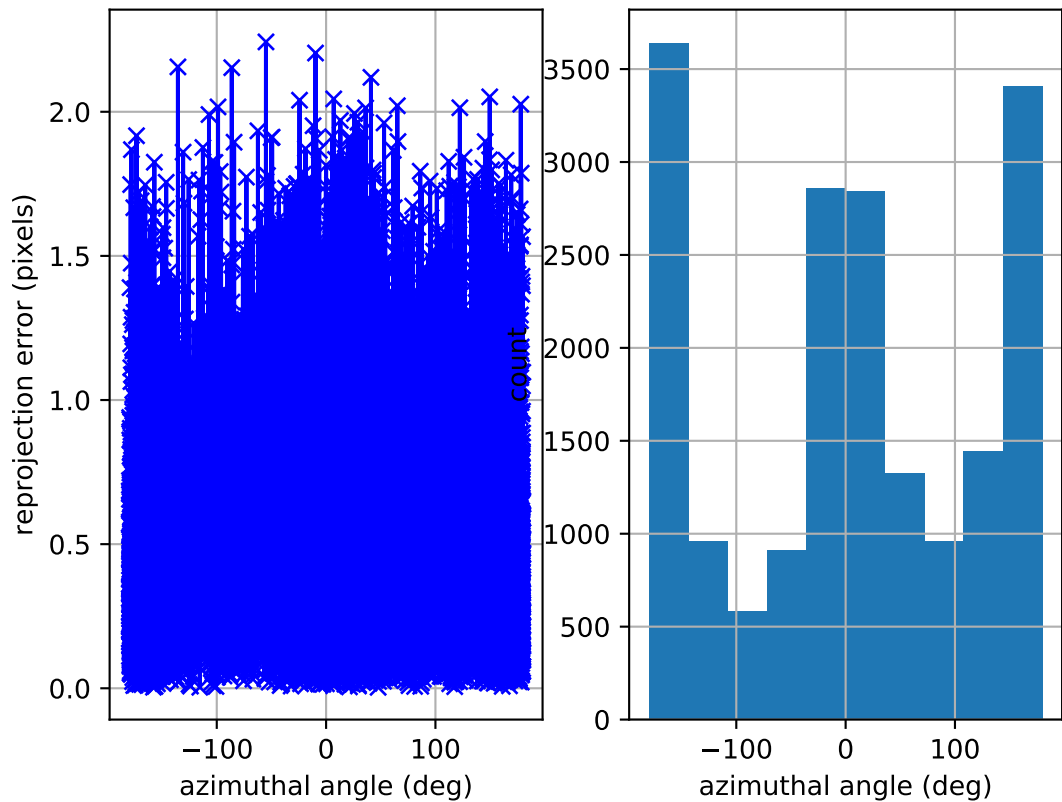
cam3: reprojection errors



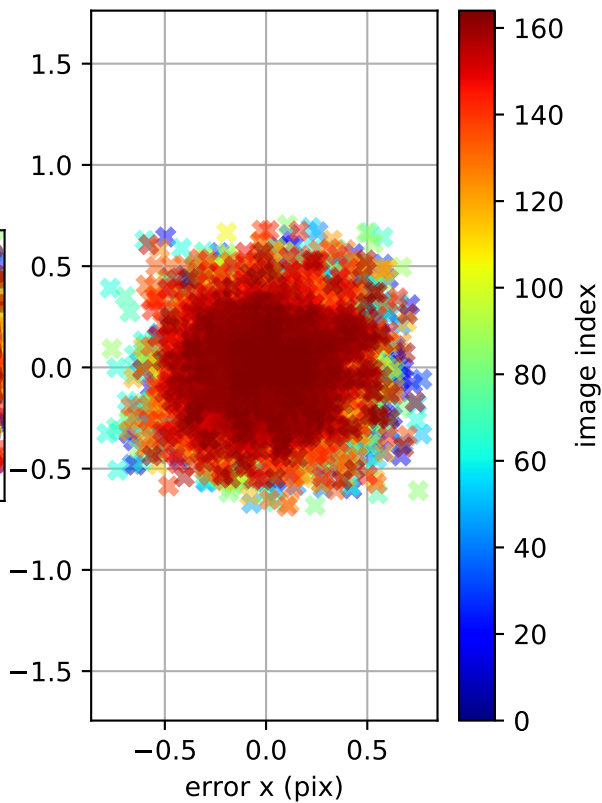
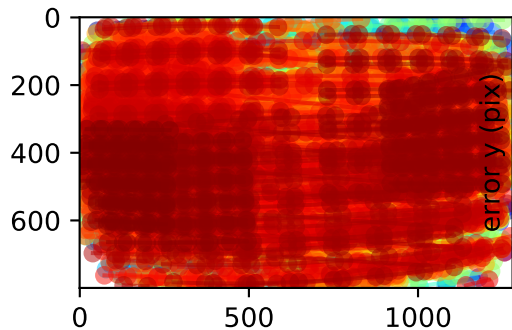
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

