

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.0441657 0.08121441 -0.00135821 -0.00245069] +- [0.00091585 0.00201231 0.00008509 0.00005053]

projection: [1034.86278431 1033.47800271 629.70125104 357.60071019] +- [0.14026016 0.14562211 0.00401118 0.15765501]

reprojection error: [-0.000015, -0.000066] +- [0.525314, 0.451482]

cam1 (/prophesee/right/events):

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

distortion: [-0.04914575 0.08551275 -0.0000454 -0.00087687] +- [0.00097025 0.00216936 0.00008402 0.0000507]

projection: [1035.07712803 1034.76733944 632.04513322 359.48878546] +- [0.13592912 0.14206264 0.01059935 0.14007686]

reprojection error: [0.000069, -0.000079] +- [0.529067, 0.454079]

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

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

distortion: [-0.39785222 0.16525157 0.00054595 0.00064107] +- [0.00052566 0.00095202 0.00005773 0.00003157]

projection: [1060.71508931 1059.88398285 672.16342254 330.45960904] +- [0.13873626 0.13917451 0.01059155 0.21771457]

reprojection error: [0.000156, -0.000096] +- [0.304745, 0.250757]

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

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

distortion: [-0.39614261 0.15934422 0.00025056 0.00140993] +- [0.00045182 0.00074494 0.00005555 0.00003397]

projection: [1055.58864299 1055.348377 668.81922664 323.42784805] +- [0.13762189 0.1414371 0.03269755 0.21463277]

reprojection error: [0.000185, -0.000116] +- [0.306363, 0.233959]

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

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

distortion: [-0.41903413 0.19567815 0.00091149 0.00030483] +- [0.0008176 0.00215854 0.00005682 0.00003719]

projection: [1268.56022264 1267.34933732 649.36902423 359.93799316] +- [0.13693374 0.1398059 0.0061315 0.09103613]

reprojection error: [0.000062, -0.000089] +- [0.427610, 0.408086]

baseline T_1_0:

q: [-0.00014654 0.00234324 -0.00006045 0.99999724] +- [0.00019118 0.00006003 0.00003732]

t: [-0.12023168 0.0008363 0.00101191] +- [0.00004117 0.00004048 0.000127]

baseline T_2_1:

q: [-0.00018085 -0.00245988 -0.00456545 0.99998654] +- [0.00027171 0.00005829 0.00003597]

t: [0.12057225 0.06913423 0.00258229] +- [0.00003804 0.00003785 0.00013082]

baseline T_3_2:

q: [-0.00028222 -0.00077495 0.00053522 0.99999952] +- [0.00030501 0.00006775 0.00003187]

t: [-0.12005103 -0.00001994 0.00106148] +- [0.00003383 0.00003251 0.00013205]

baseline T_4_3:

q: [0.00247093 0.00316245 0.00023538 0.99999192] +- [0.00024216 0.0000648 0.00003136]

t: [0.08889905 0.00621568 0.00300468] +- [0.0000331 0.00003099 0.00012245]

Target configuration

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Type: aprilgrid

Tags:

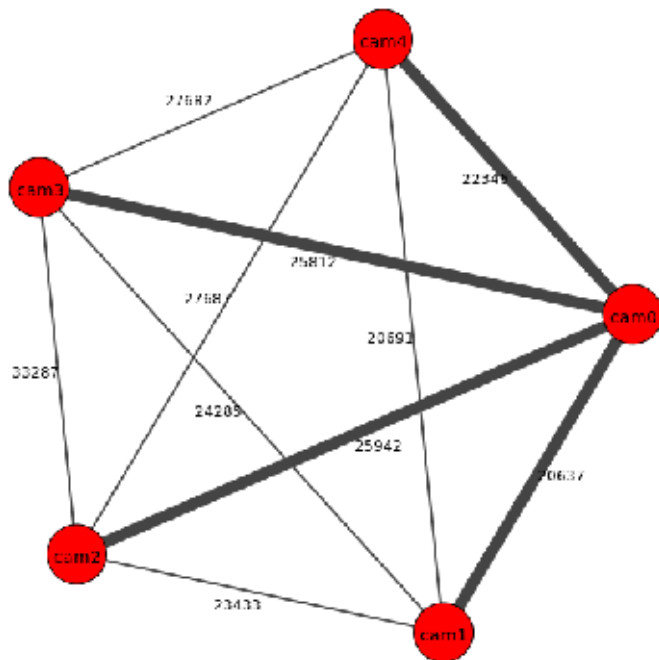
Rows: 5

Cols: 7

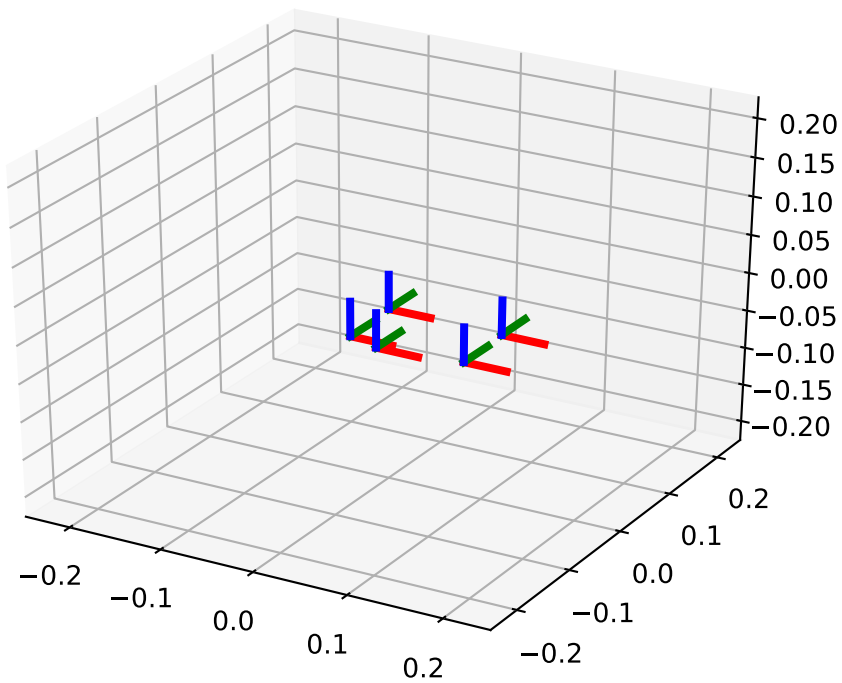
Size: 0.04 [m]

Spacing 0.01 [m]

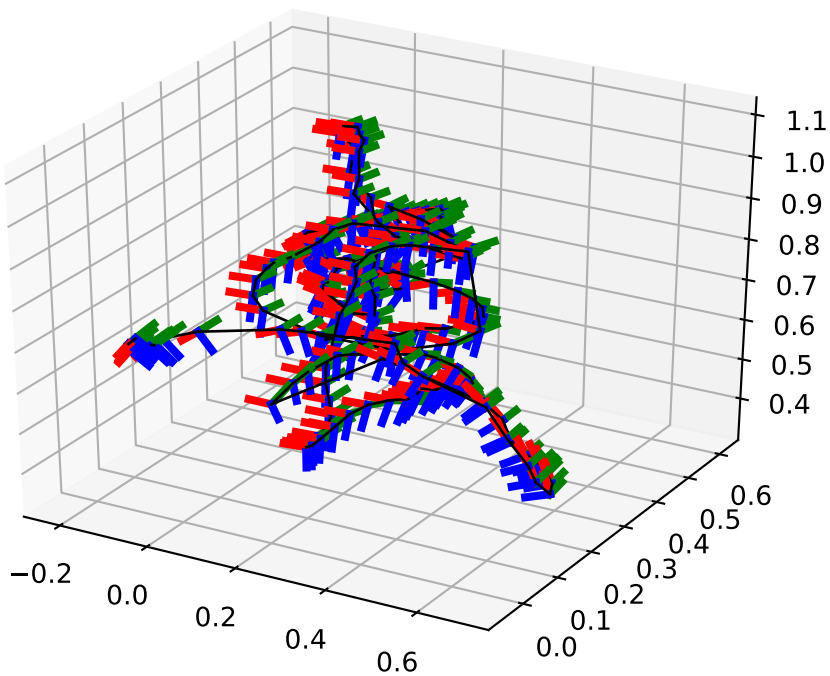
Inter-camera observations graph (edge weight=#mutual obs.)



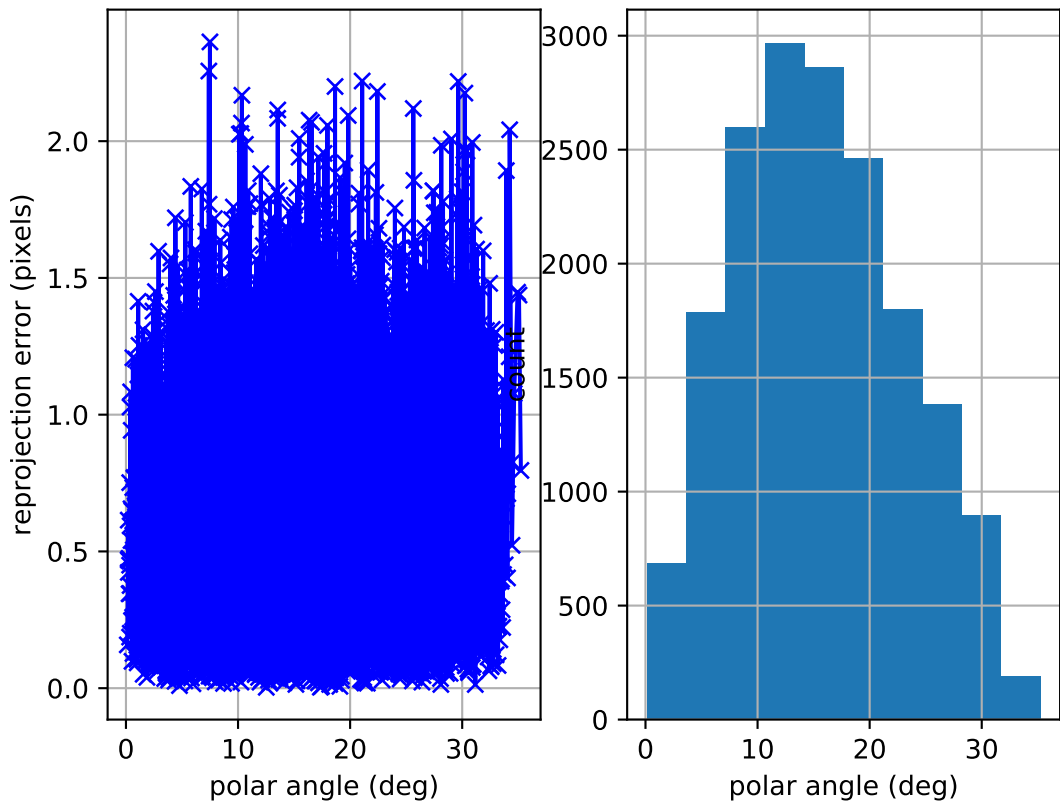
camera system



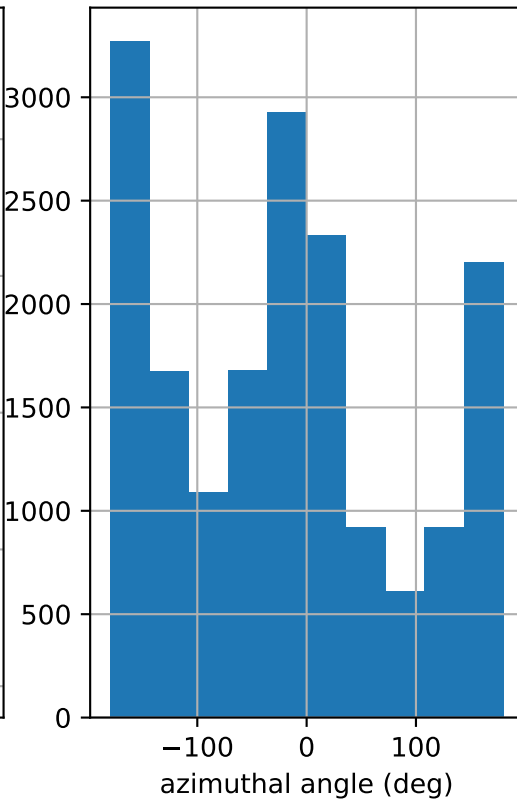
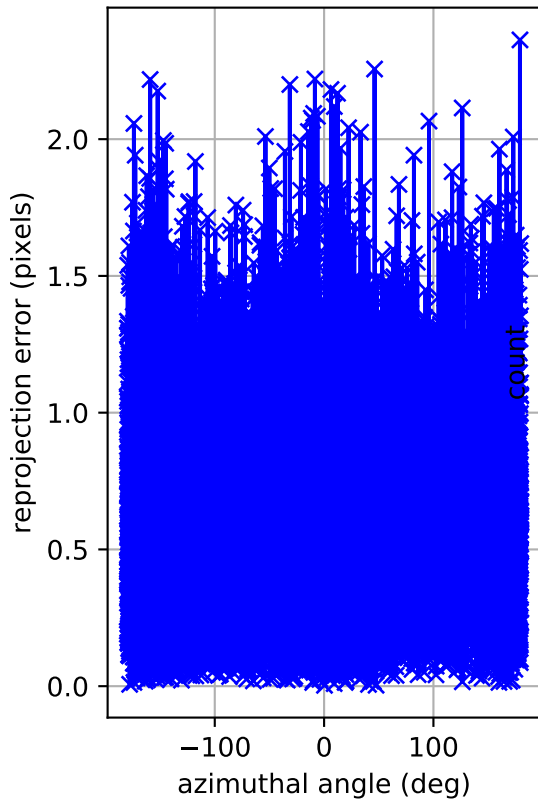
cam0: estimated poses



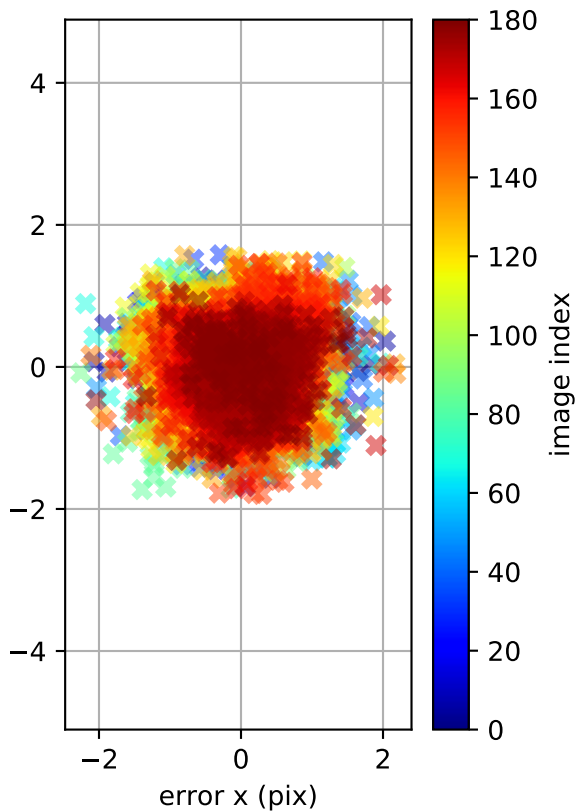
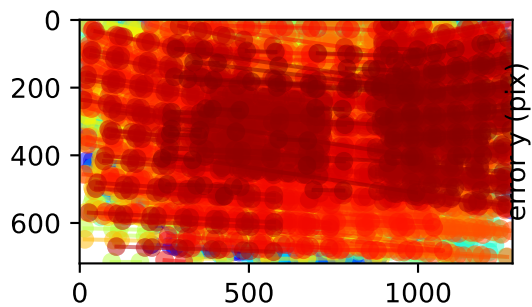
cam0: polar error



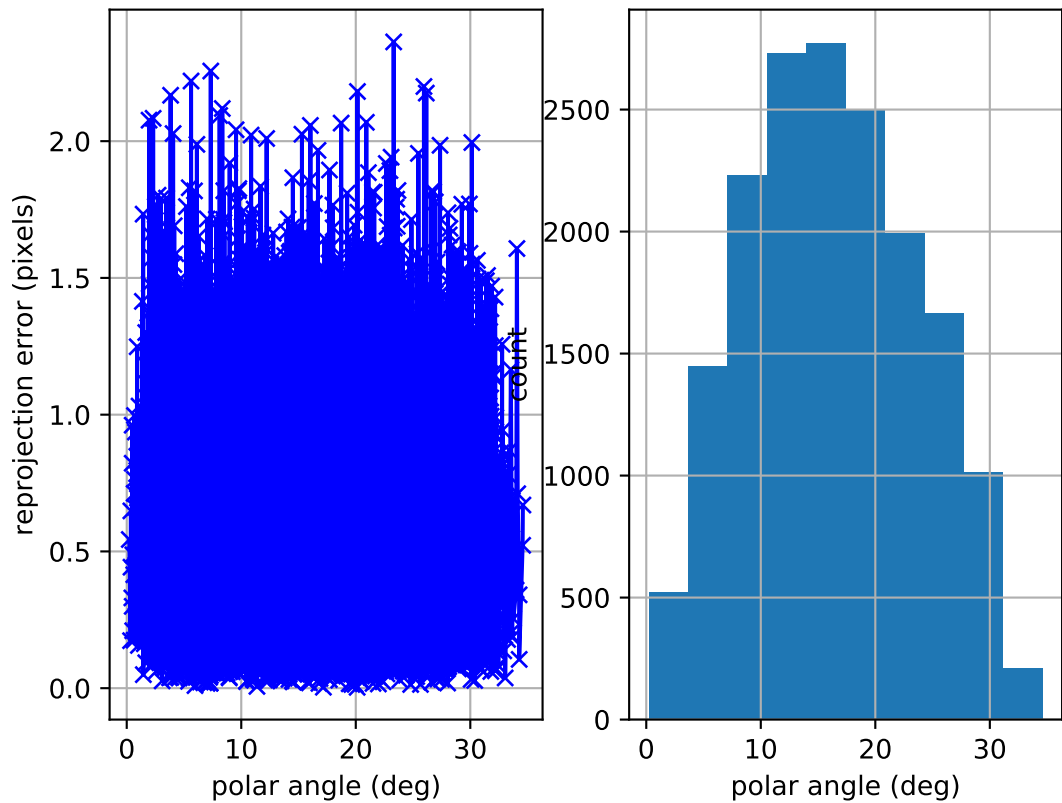
cam0: azimuthal error



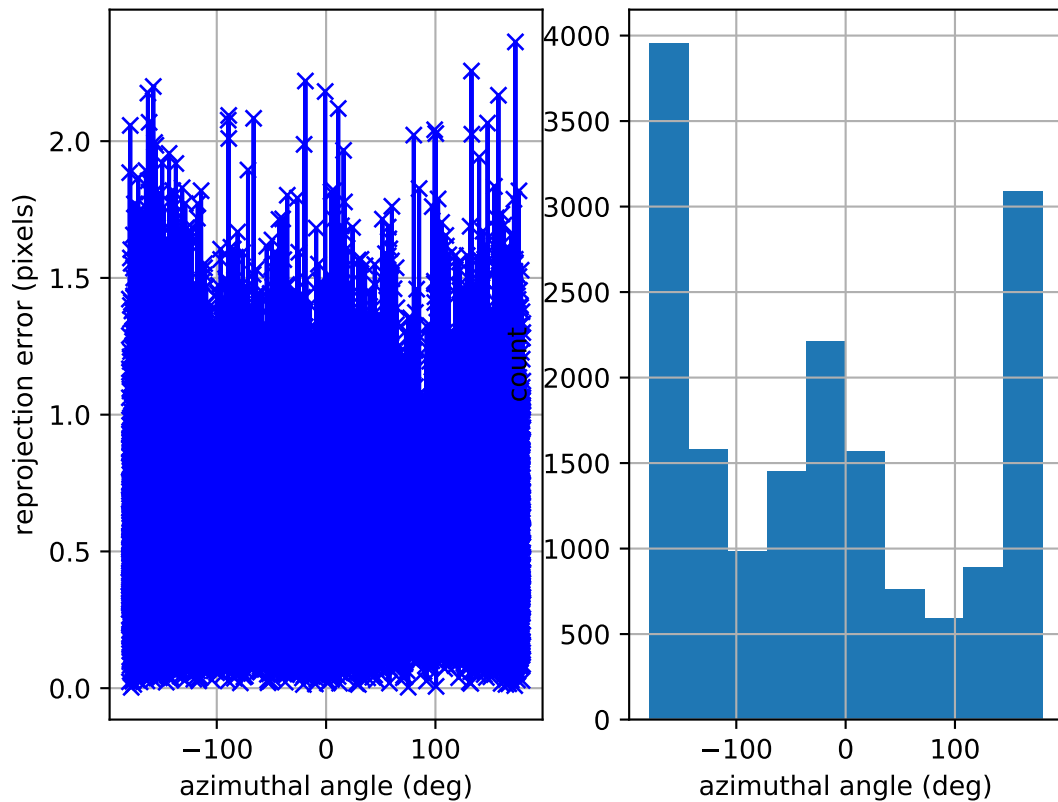
cam0: reprojection errors



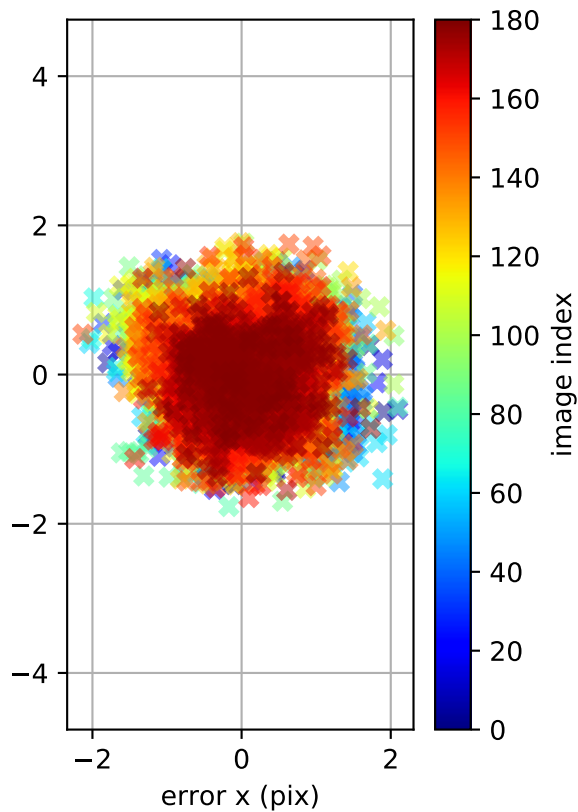
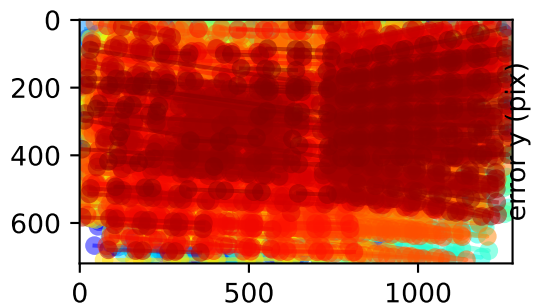
cam1: polar error



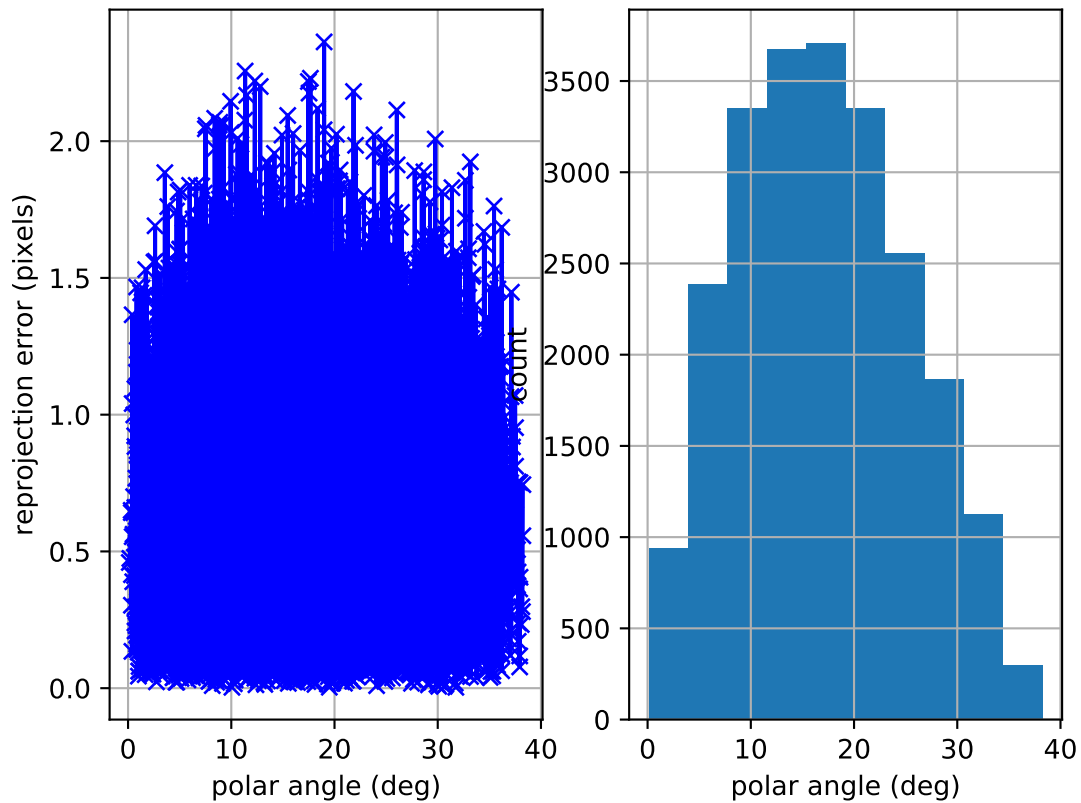
cam1: azimuthal error



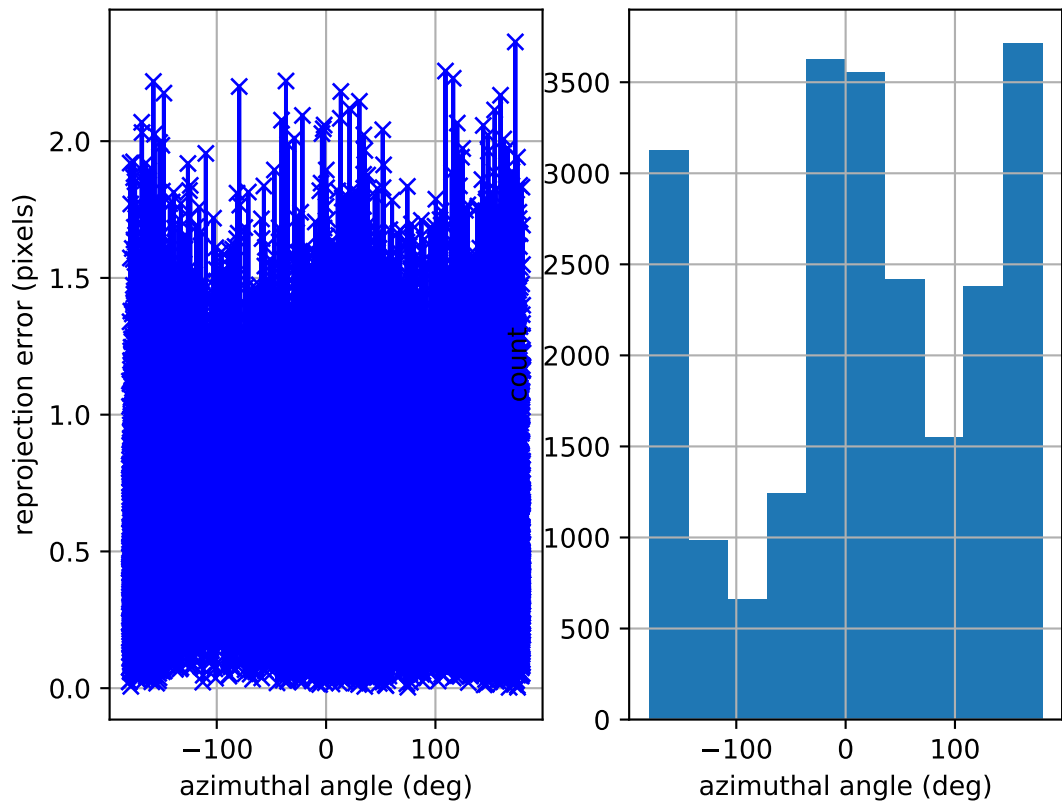
cam1: reprojection errors



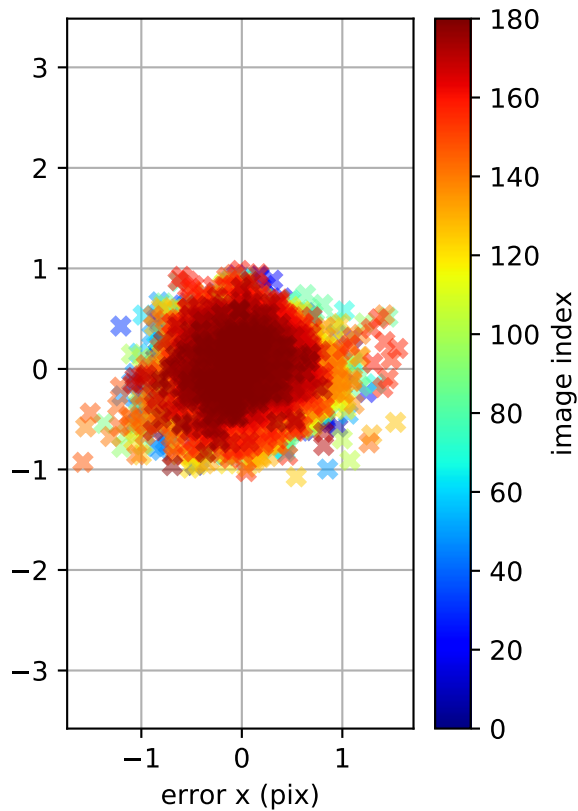
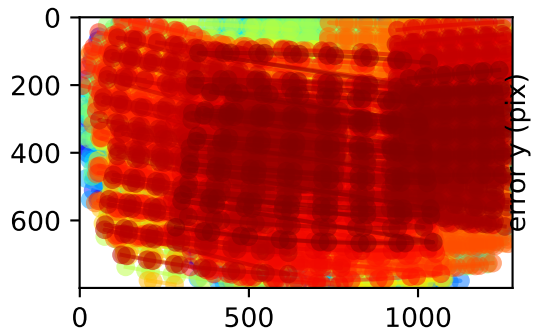
cam2: polar error



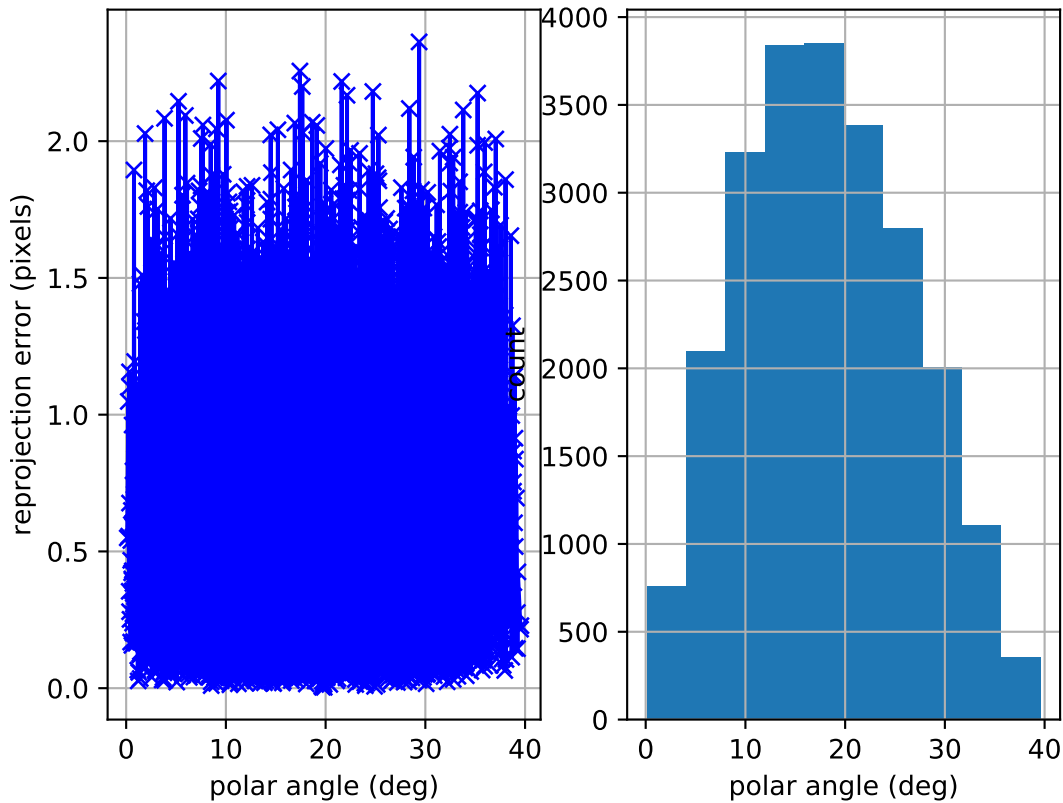
cam2: azimuthal error



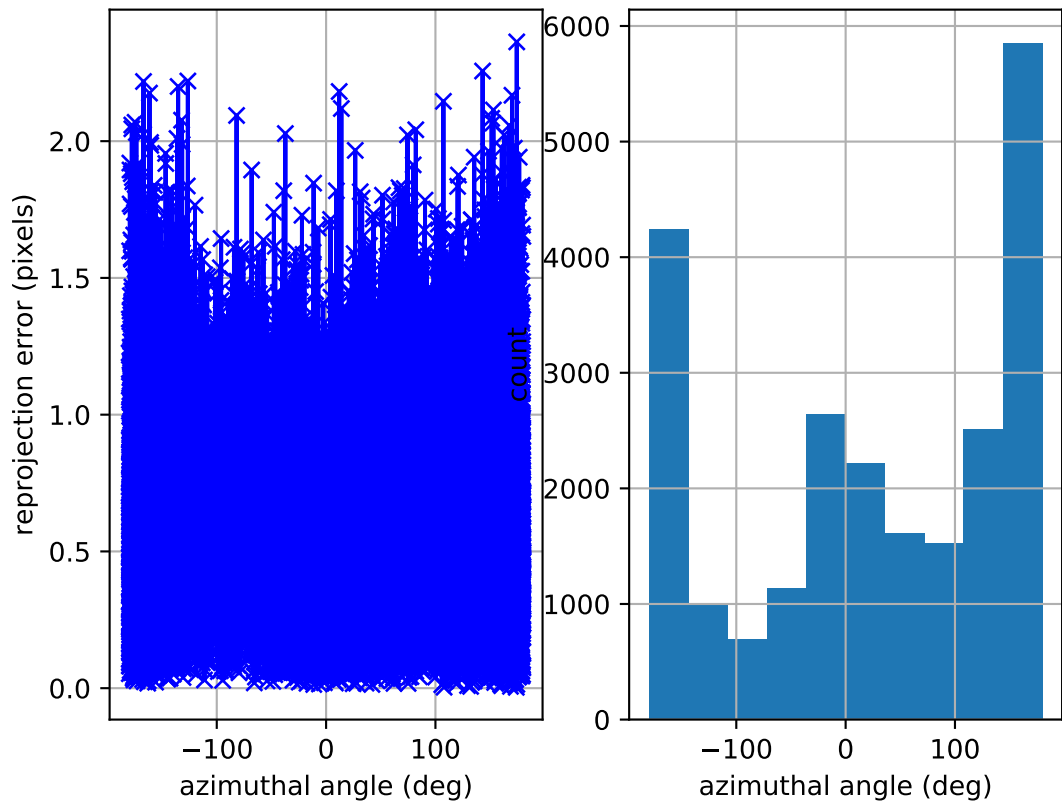
cam2: reprojection errors



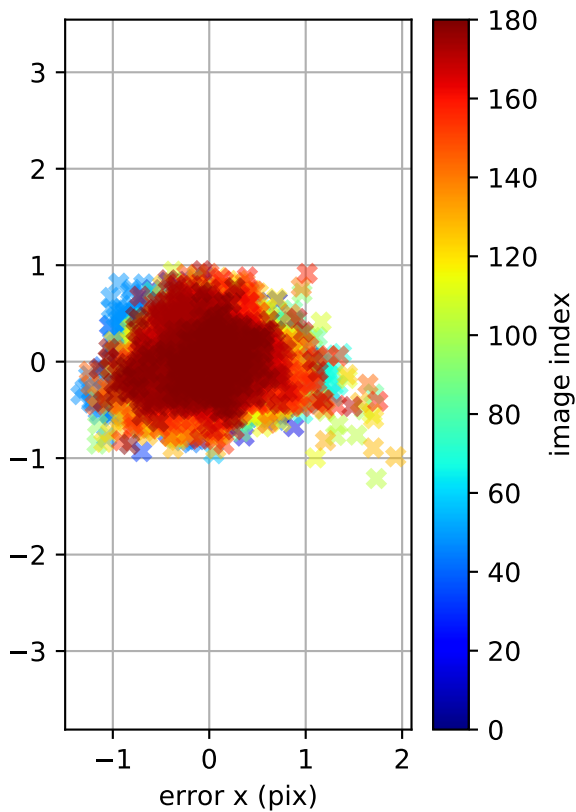
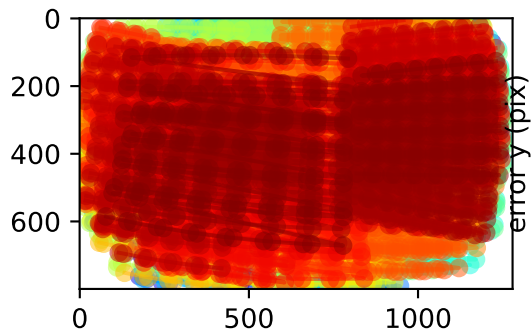
cam3: polar error



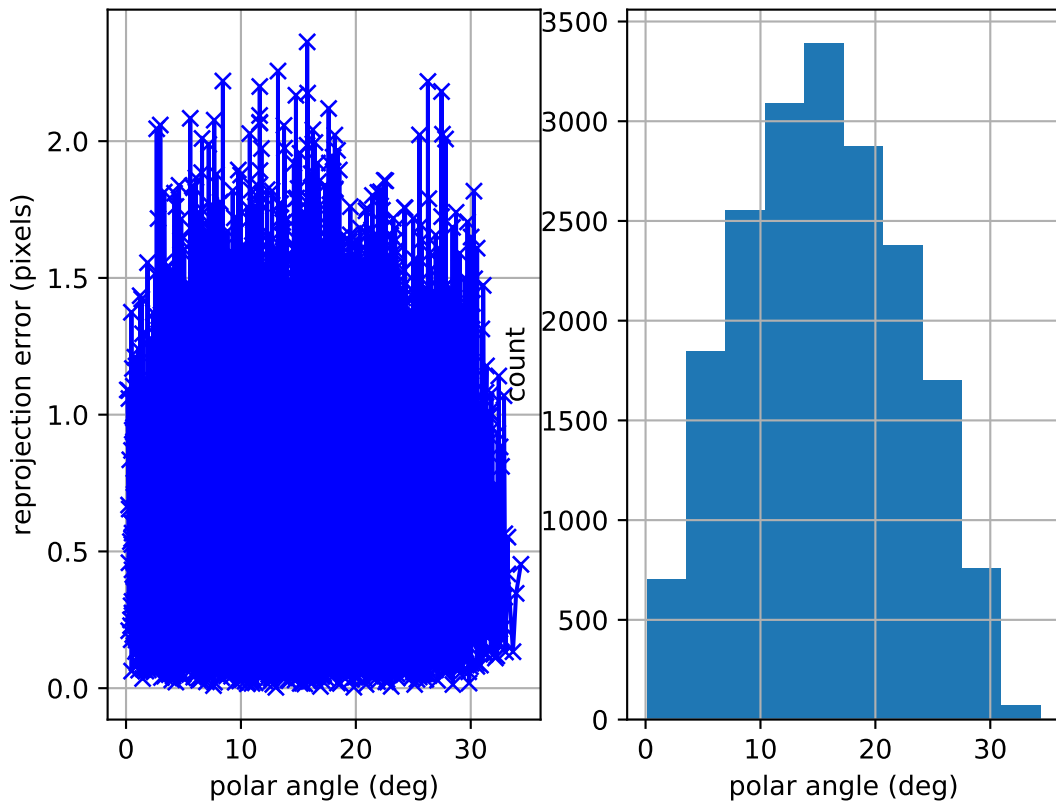
cam3: azimuthal error



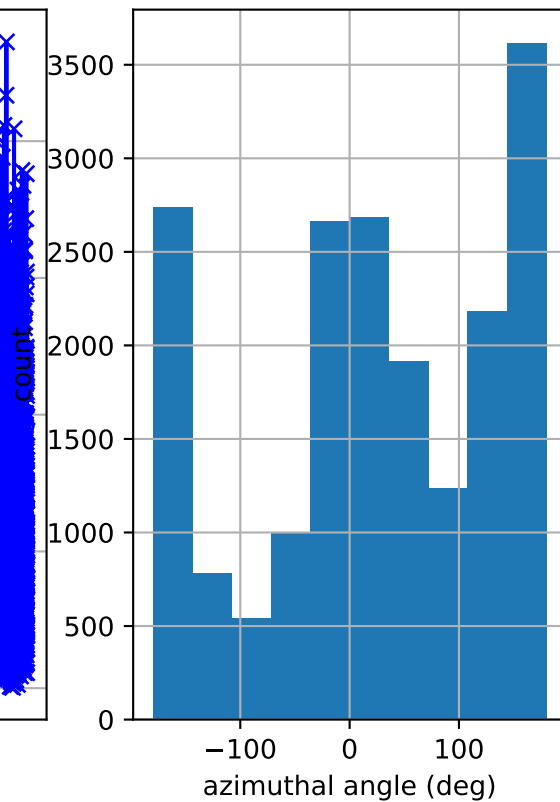
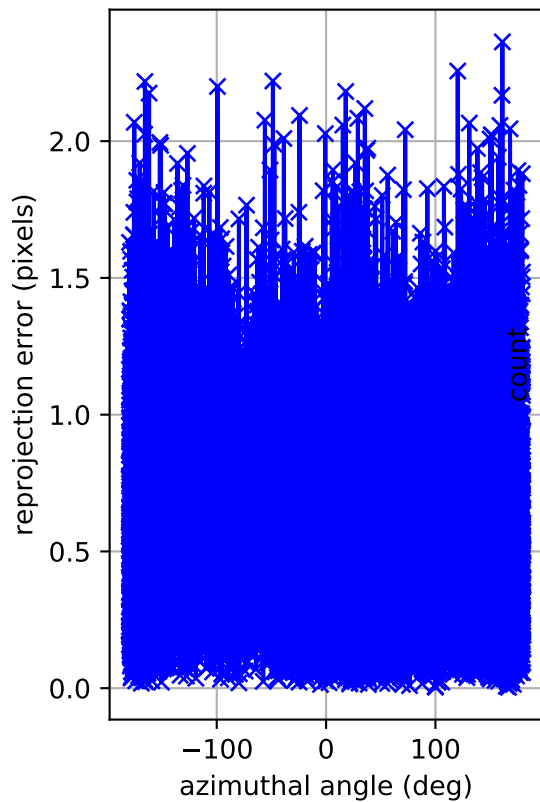
cam3: reprojection errors



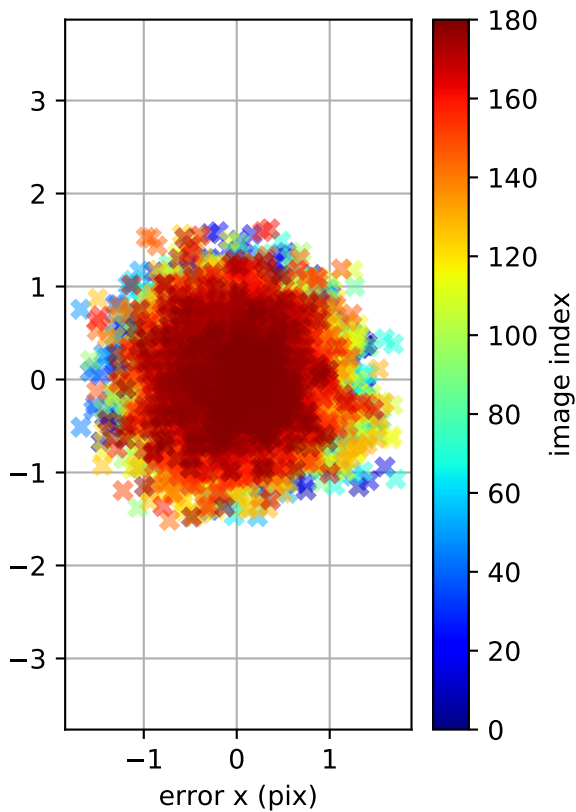
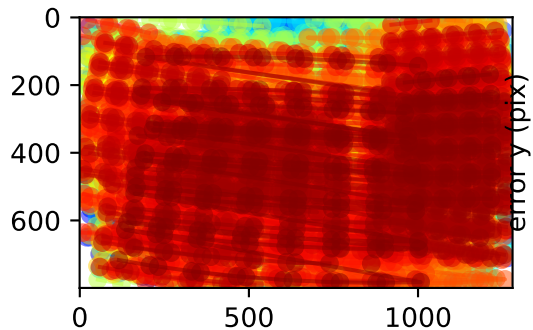
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

