

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04357214 0.07965403 -0.00053649 -0.00052506] +- [0.00106107 0.00232268 0.00010289 0.00006144]
projection: [1033.39370725 1031.9143859 636.02701332 359.2474613] +- [0.06182903 0.06309667 0.02626319
0.26164531]

reprojection error: [0.000035, 0.000111] +- [0.554096, 0.431751]

cam1 (/prophesee/right/events):

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

distortion: [-0.04957922 0.08010054 0.00063286 0.00065099] +- [0.00108462 0.00242293 0.00010196 0.00006286]
projection: [1032.16627257 1030.86961564 636.63418984 362.53652701] +- [0.11294503 0.11591934 0.01718093
0.24897422]

reprojection error: [0.000032, 0.000011] +- [0.558202, 0.444654]

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

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

distortion: [-0.39658729 0.16509532 0.00012936 0.00041478] +- [0.0006215 0.00117884 0.00006075 0.0000415]
projection: [1059.60070175 1058.64225845 676.12198996 333.10060755] +- [0.17669473 0.18476762 0.03039841
0.22738485]

reprojection error: [0.000019, -0.000092] +- [0.165372, 0.148391]

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

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

distortion: [-0.39445609 0.15664605 0.00006716 0.00115353] +- [0.00051148 0.00082647 0.00005989 0.0000406]
projection: [1054.96440911 1054.33606056 672.03182071 325.16204643] +- [0.1777112 0.18513598 0.02224113
0.22506935]

reprojection error: [0.000007, -0.000022] +- [0.182112, 0.148563]

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

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

distortion: [-0.41285396 0.18058514 0.00091666 0.00017712] +- [0.00079478 0.0019811 0.0000651 0.00004357]
projection: [1265.55870118 1264.34662721 649.27761928 359.29828652] +- [0.15067502 0.1560026 0.02648167
0.2401756]

reprojection error: [-0.000070, 0.000041] +- [0.585595, 0.449877]

baseline T_1_0:

q: [-0.00108113 0.00187879 -0.00017192 0.99999764] +- [0.00037035 0.00007446 0.00004221]

t: [-0.12014566 0.00090839 -0.00109686] +- [0.00005193 0.00005427 0.00011968]

baseline T_2_1:

q: [0.00002598 -0.00311699 -0.00511776 0.99998205] +- [0.00034669 0.00007715 0.00003934]

t: [0.12007045 0.06915915 0.00463539] +- [0.00004905 0.00004964 0.00017718]

baseline T_3_2:

q: [0.00007916 -0.00156439 0.00042784 0.99999868] +- [0.00031628 0.0000791 0.00003402]

t: [-0.11986758 -0.00007581 0.00122642] +- [0.00004476 0.00004132 0.00020478]

baseline T_4_3:

q: [0.00364354 0.00179583 0.00012872 0.99999174] +- [0.00032479 0.00006323 0.0000332]

t: [0.08869088 0.00623717 0.00218575] +- [0.00003952 0.00003819 0.00019209]

Target configuration

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Type: aprilgrid

Tags:

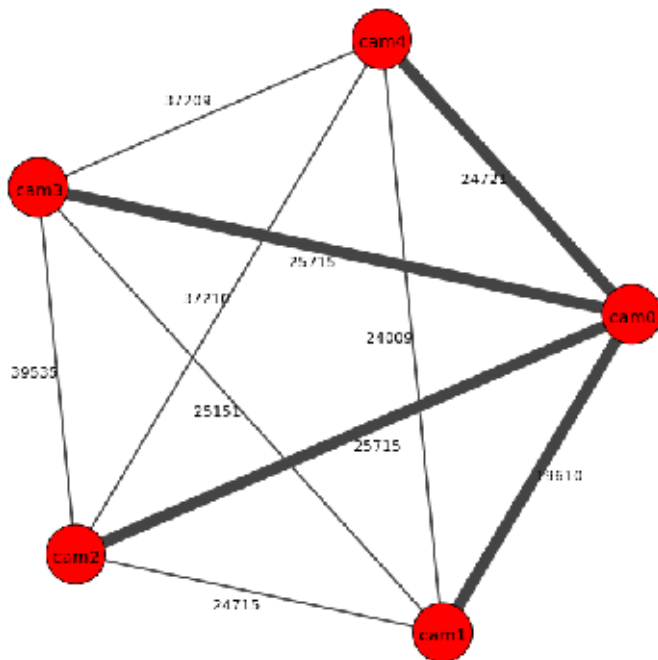
Rows: 5

Cols: 7

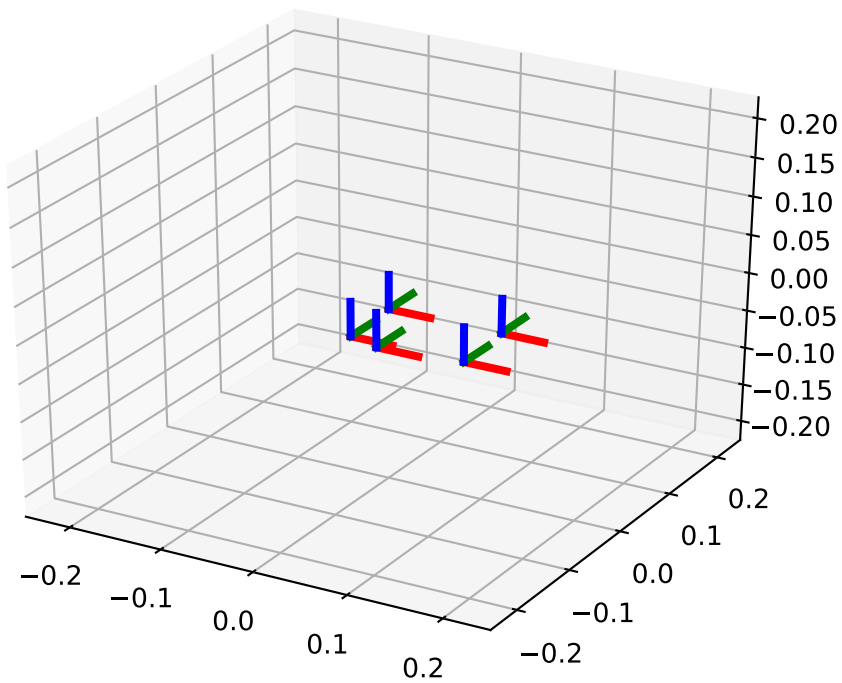
Size: 0.04 [m]

Spacing 0.01 [m]

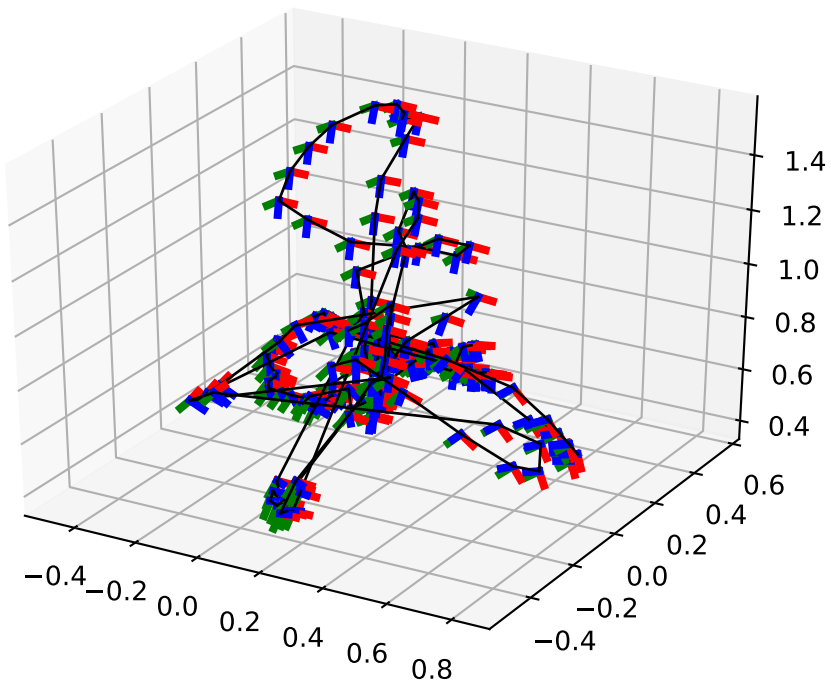
Inter-camera observations graph (edge weight=#mutual obs.)



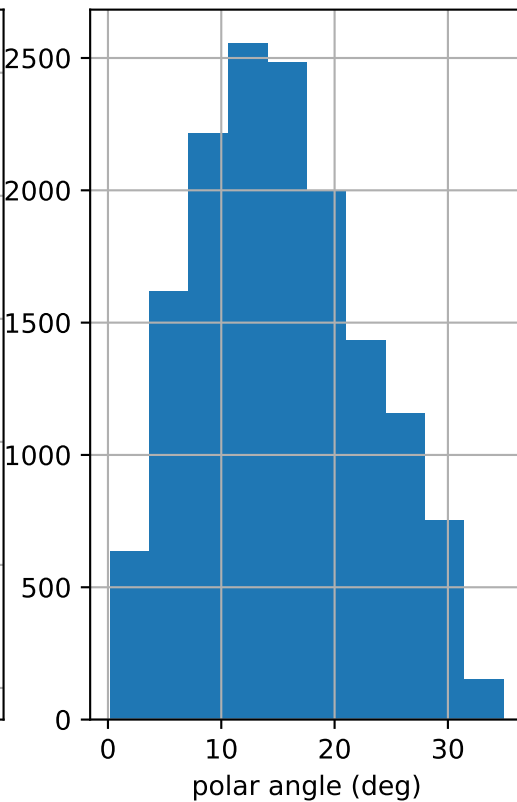
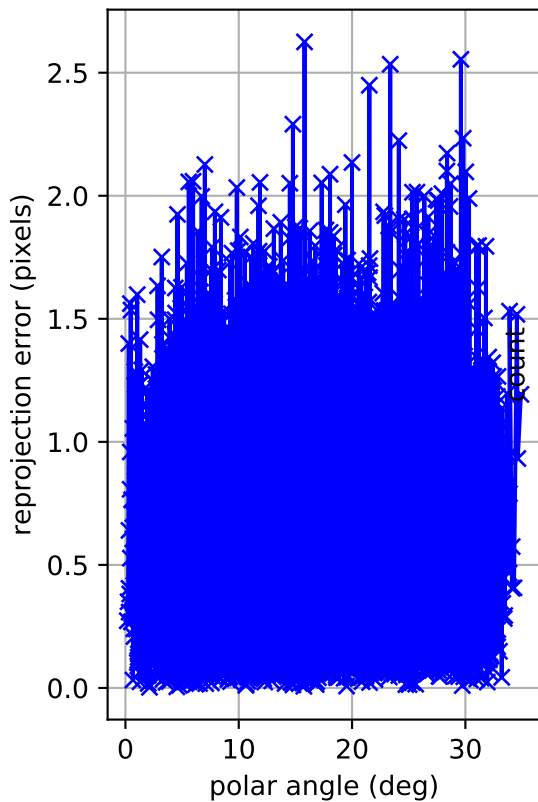
camera system



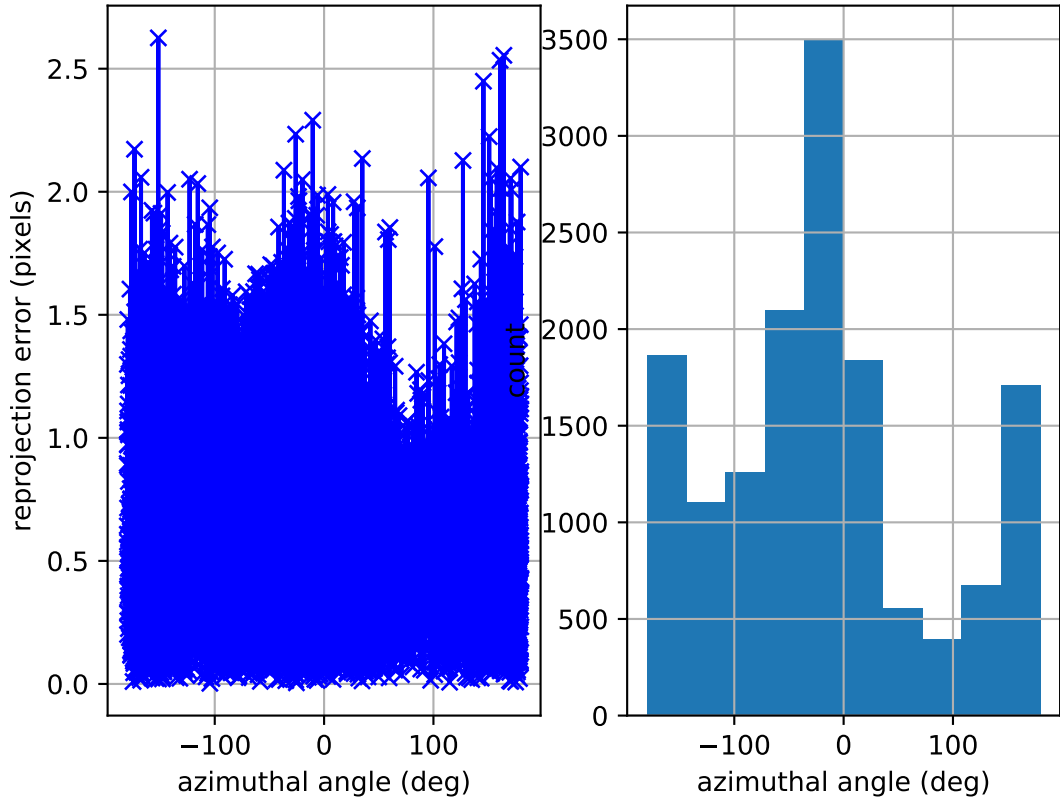
cam0: estimated poses



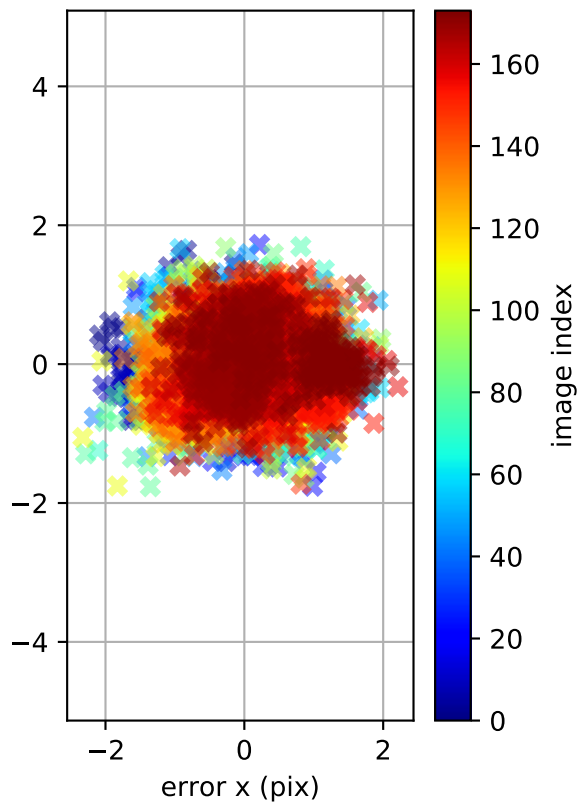
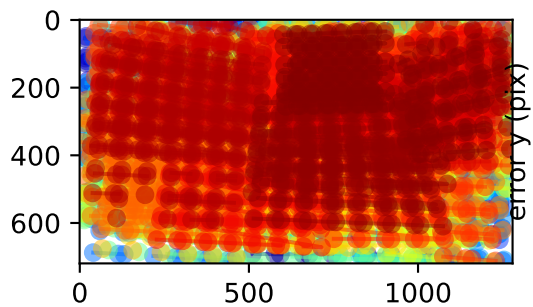
cam0: polar error



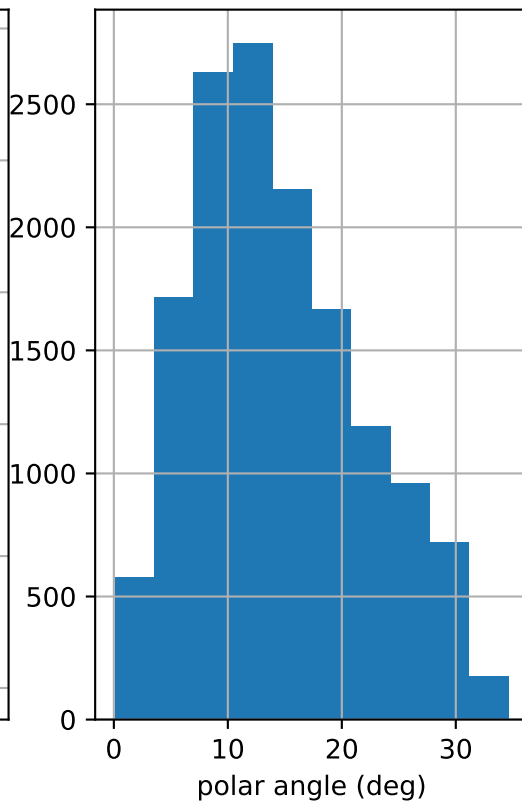
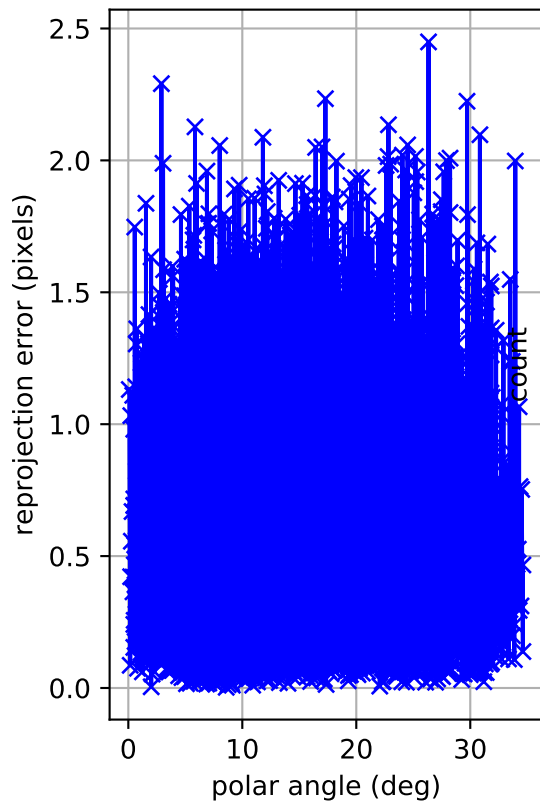
cam0: azimuthal error



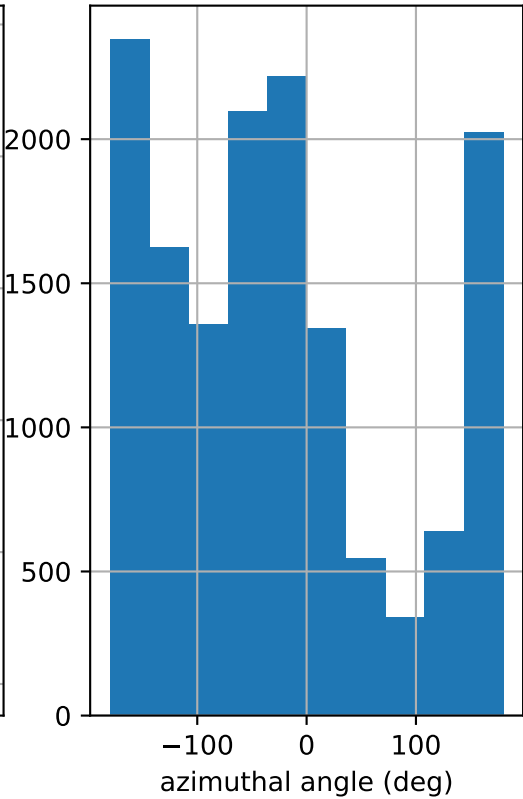
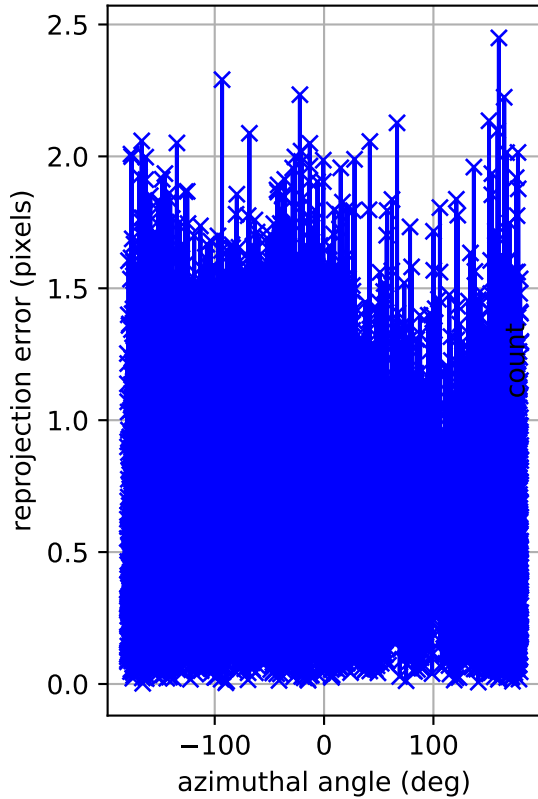
cam0: reprojection errors



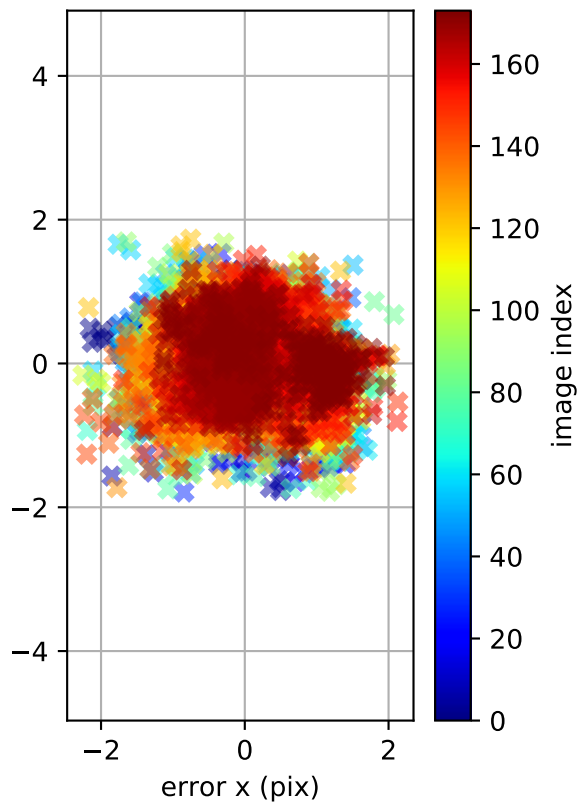
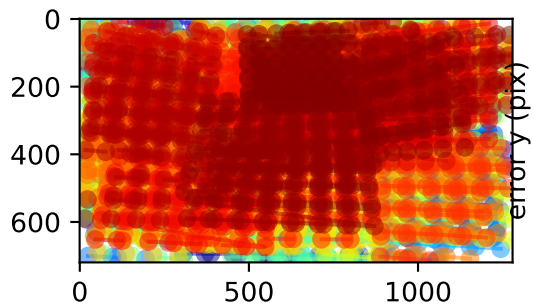
cam1: polar error



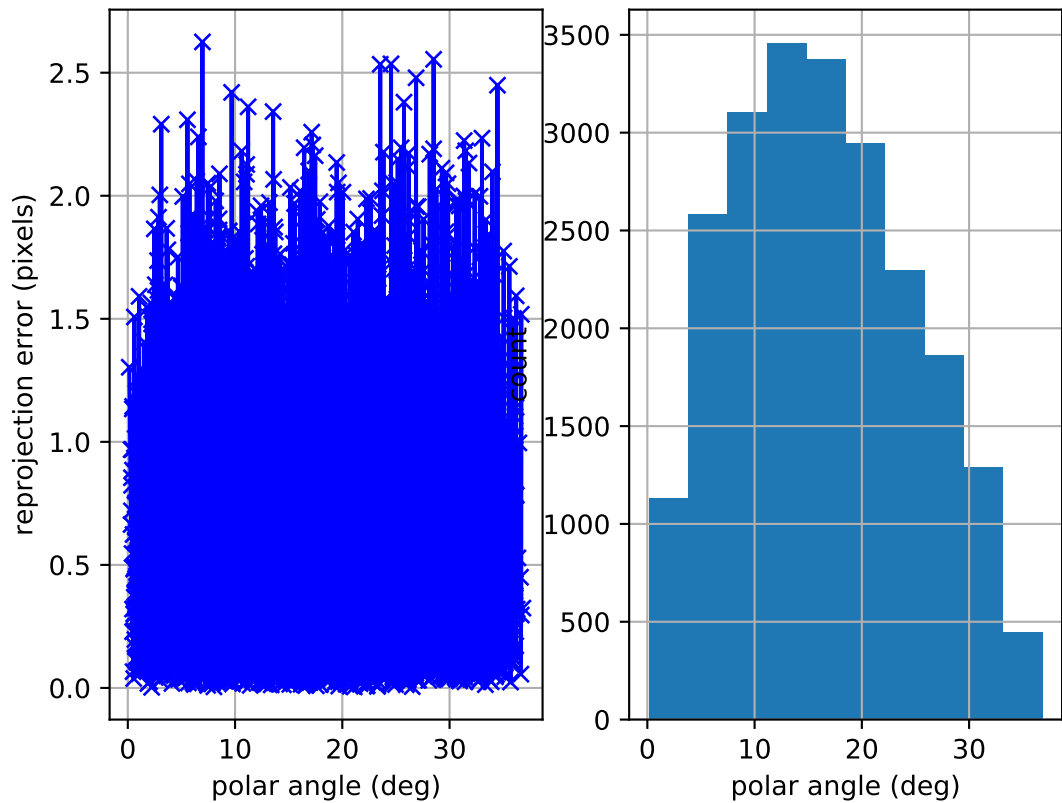
cam1: azimuthal error



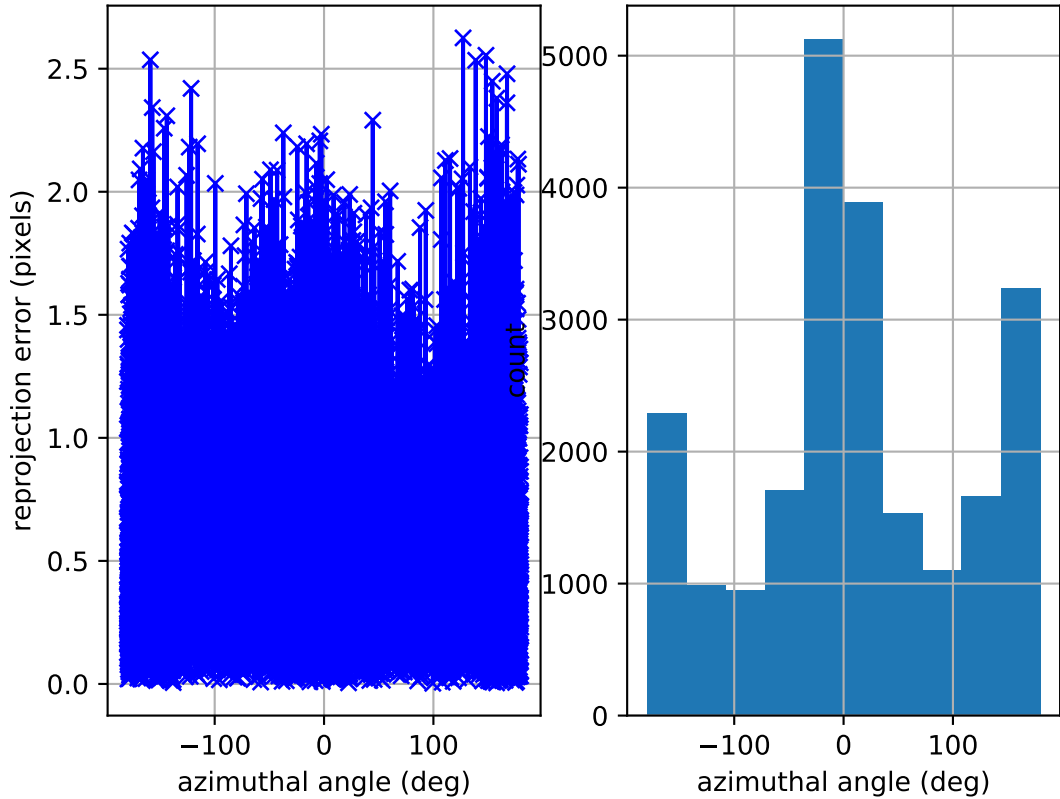
cam1: reprojection errors



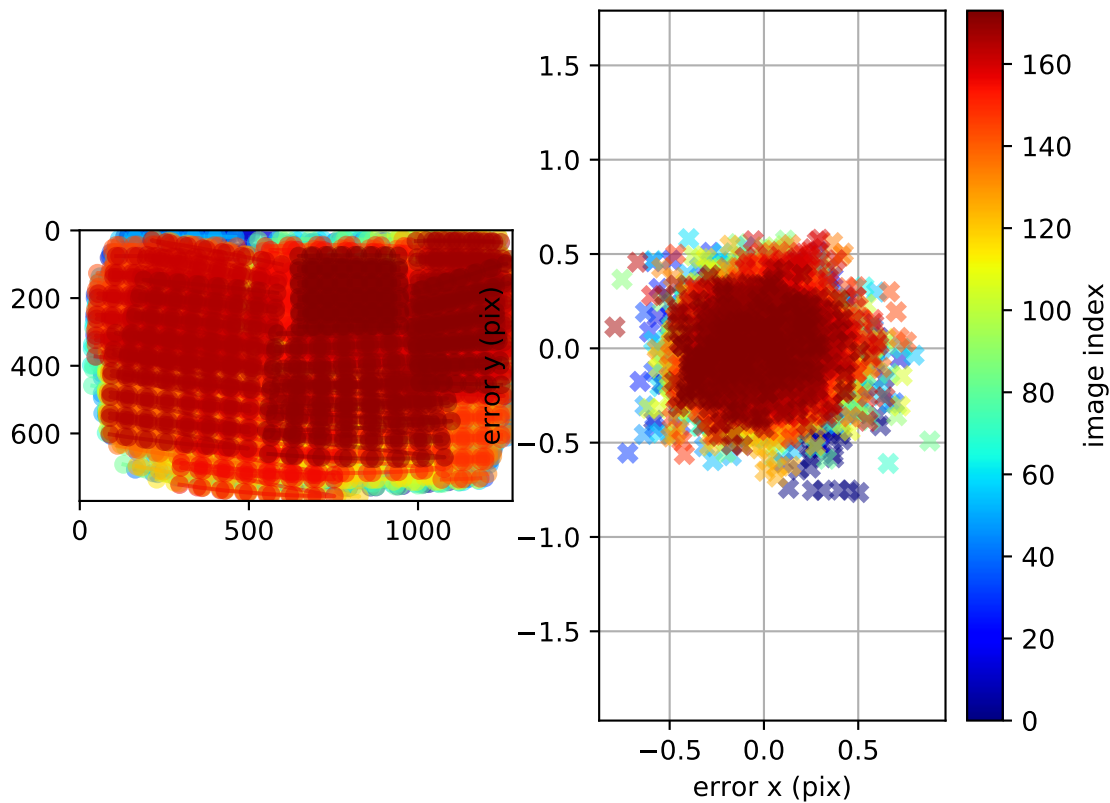
cam2: polar error



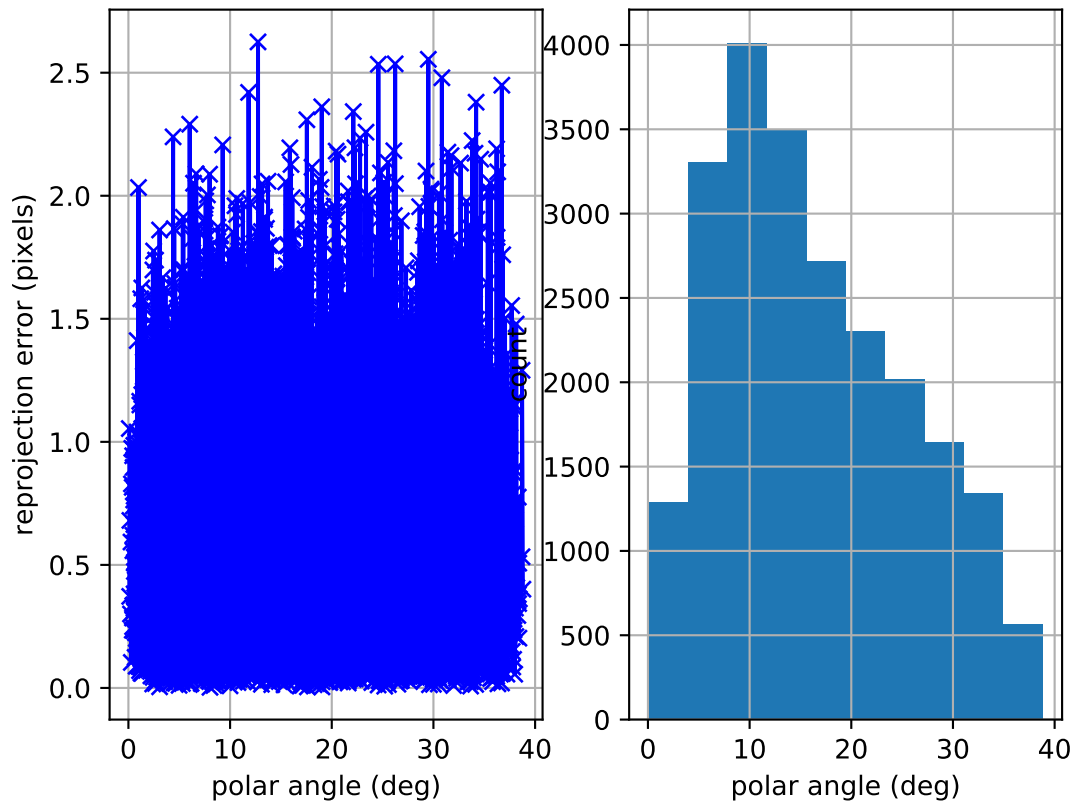
cam2: azimuthal error



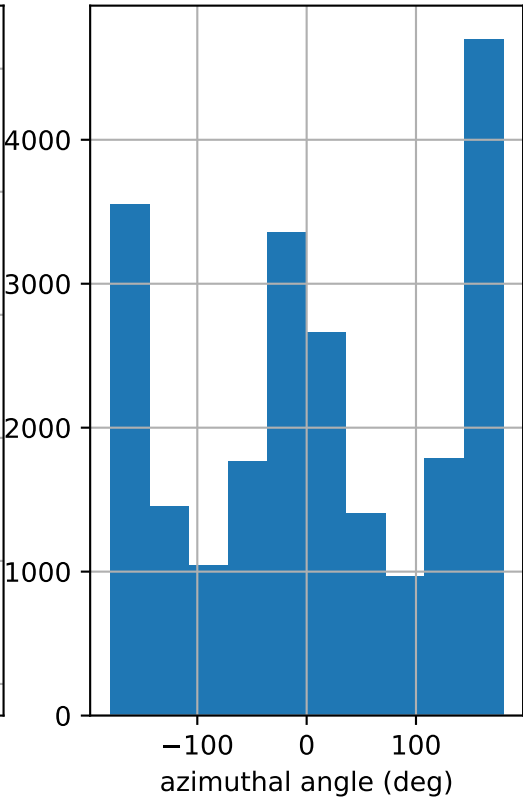
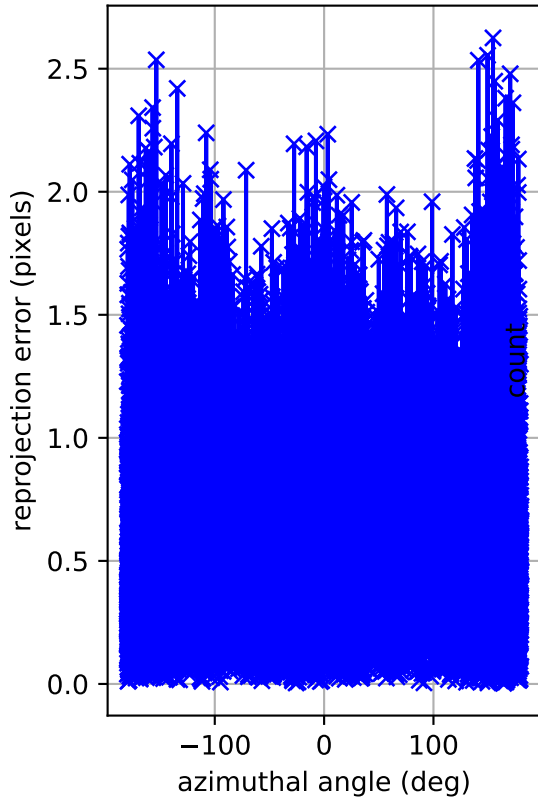
cam2: reprojection errors



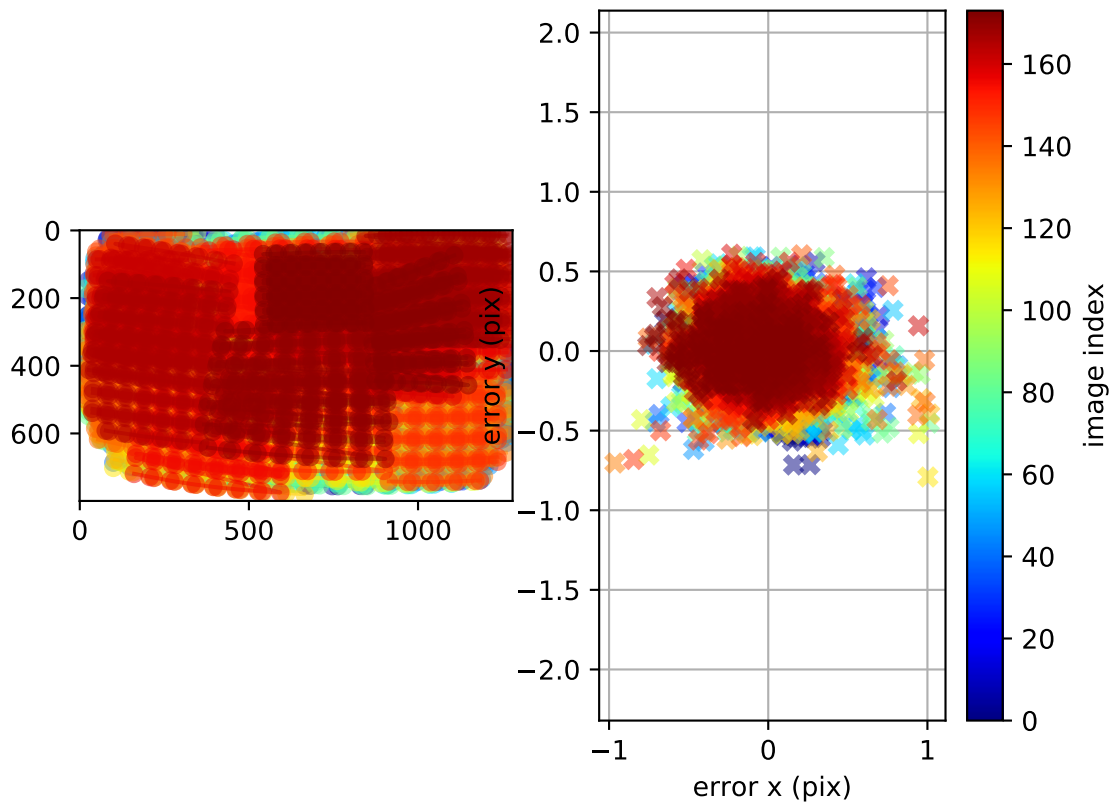
cam3: polar error



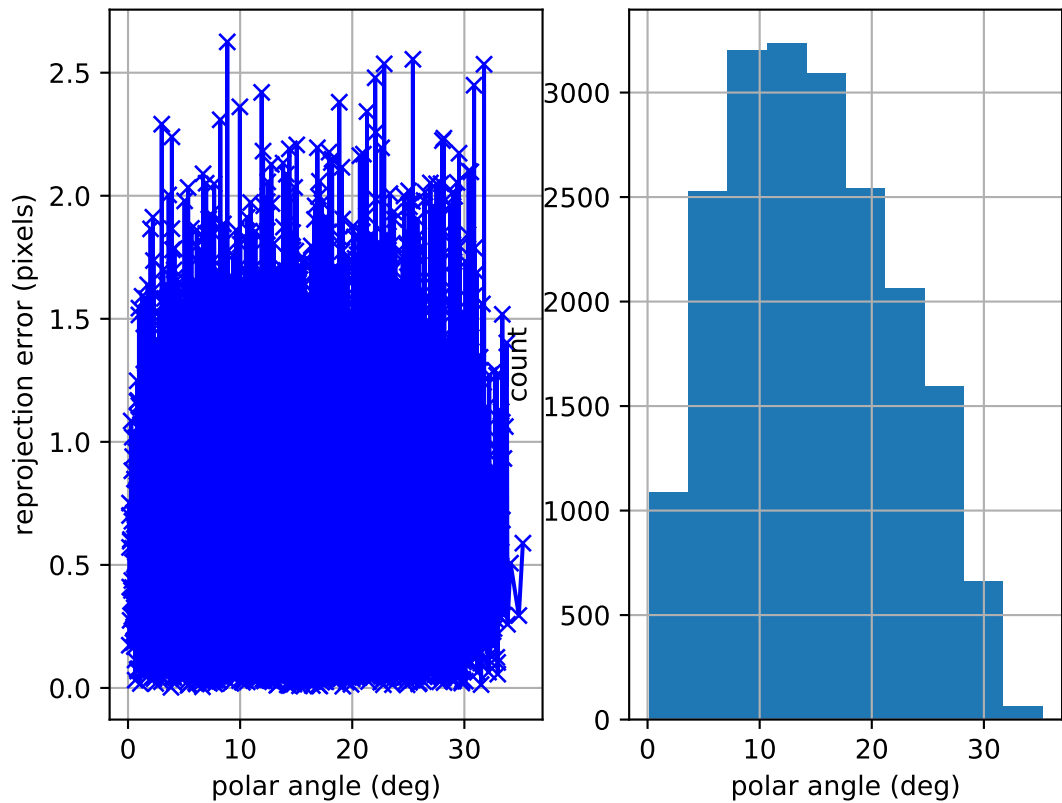
cam3: azimuthal error



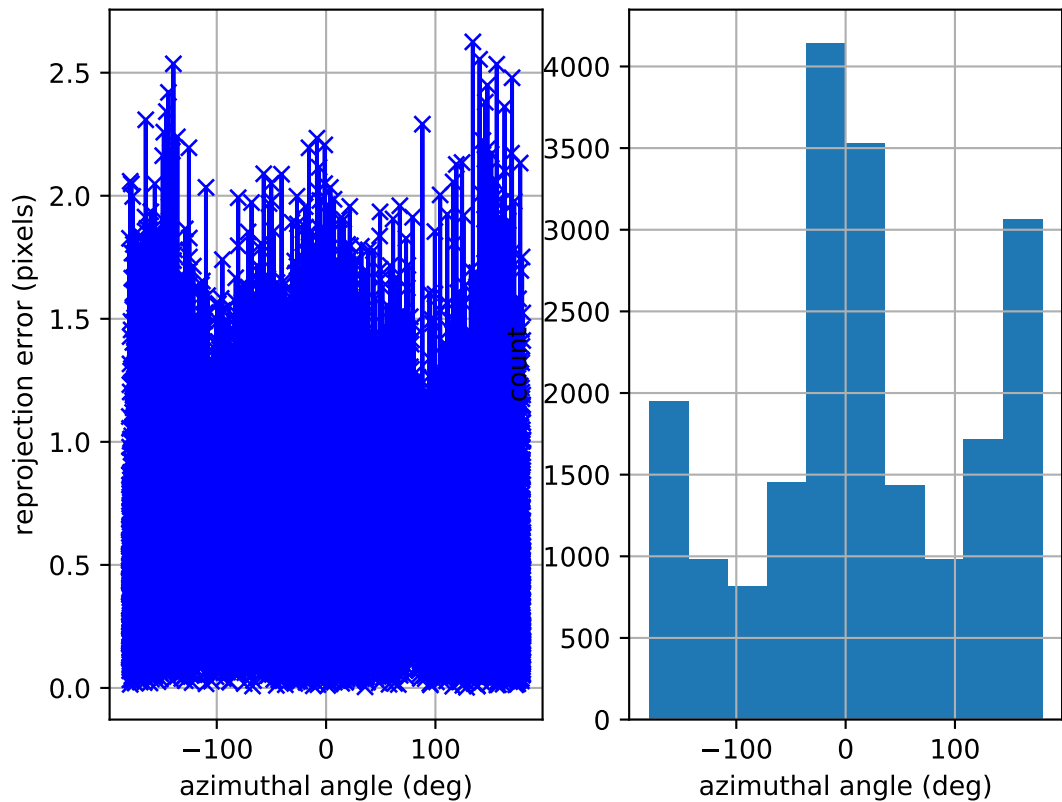
cam3: reprojection errors



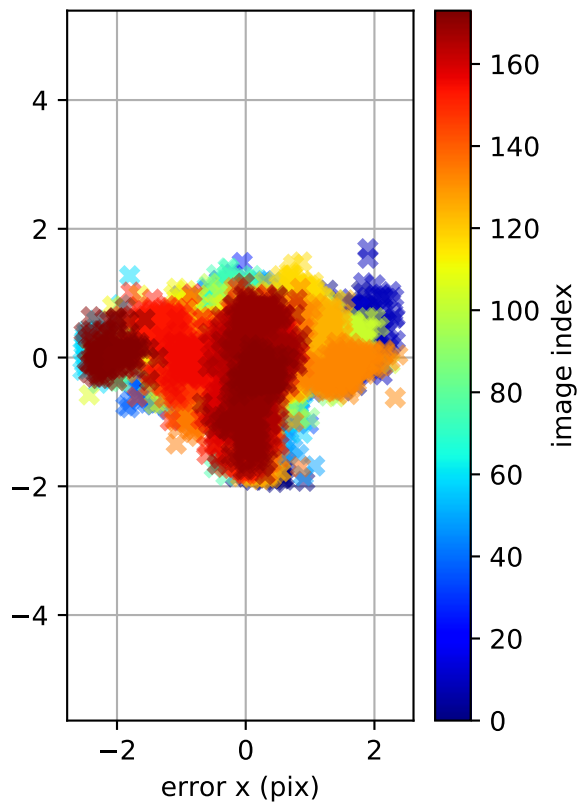
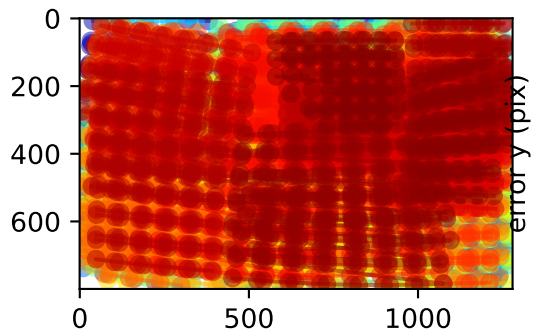
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

