

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.0435413 0.08400601 -0.0003624 0.00014401] +- [0.00089144 0.00190007 0.00008303 0.00006668]
projection: [1034.1062453 1034.11057937 638.35519987 360.26783939] +- [0.12034396 0.12129227 0.03457053 0.1611331]

reprojection error: [-0.000100, 0.000022] +- [0.699313, 0.347247]

cam1 (/prophesee/right/events):

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

distortion: [-0.04606521 0.07556439 0.00087577 0.00076602] +- [0.00088979 0.00187006 0.00007324 0.00006435]
projection: [1033.63490155 1033.75116493 639.07693333 364.12465405] +- [0.12262355 0.12194292 0.00834441 0.05356441]

reprojection error: [-0.000025, 0.000045] +- [0.694595, 0.347914]

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

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

distortion: [-0.39091405 0.15268898 0.00005582 0.00035604] +- [0.0004612 0.00072102 0.00005802 0.00004429]
projection: [1058.94251406 1059.07424911 674.56692548 335.57280023] +- [0.11030674 0.11206708 0.02326732 0.143751]

reprojection error: [0.000167, -0.000147] +- [0.429477, 0.214149]

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

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

distortion: [-0.38891948 0.14617245 -0.00030606 0.00108216] +- [0.00038922 0.00054036 0.00005539 0.00004317]
projection: [1054.03474564 1054.49284375 671.30363727 328.77152798] +- [0.10625305 0.10955761 0.03136596 0.16087078]

reprojection error: [0.000297, -0.000196] +- [0.443115, 0.202011]

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

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

distortion: [-0.4126933 0.18149362 0.0001166 -0.00012386] +- [0.00072684 0.00168318 0.00006205 0.00004676]
projection: [1267.00289042 1266.96665102 653.83726937 366.64825182] +- [0.12225519 0.12128261 0.00272351 0.01392726]

reprojection error: [0.000244, 0.000058] +- [0.501725, 0.336984]

baseline T_1_0:

q: [-0.00078664 0.00110604 -0.00022606 0.99999905] +- [0.00015967 0.00005718 0.00003386]

t: [-0.12018297 0.00095156 -0.00027058] +- [0.00003353 0.00003068 0.00011151]

baseline T_2_1:

q: [-0.000548 -0.0051048 -0.00474674 0.99997555] +- [0.00012378 0.00004501 0.00003295]

t: [0.12024835 0.06916419 0.00308775] +- [0.00003186 0.00002955 0.00011107]

baseline T_3_2:

q: [-0.0003729 0.00028024 0.00033967 0.99999983] +- [0.0002368 0.00005843 0.00002979]

t: [-0.12001218 -0.00008188 0.00073004] +- [0.00003016 0.00002767 0.00010561]

baseline T_4_3:

q: [0.00242182 0.00259582 0.00029013 0.99999366] +- [0.00016192 0.00004861 0.00002933]

t: [0.08886606 0.00621121 0.00326196] +- [0.00002771 0.0000263 0.00010295]

Target configuration

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Type: aprilgrid

Tags:

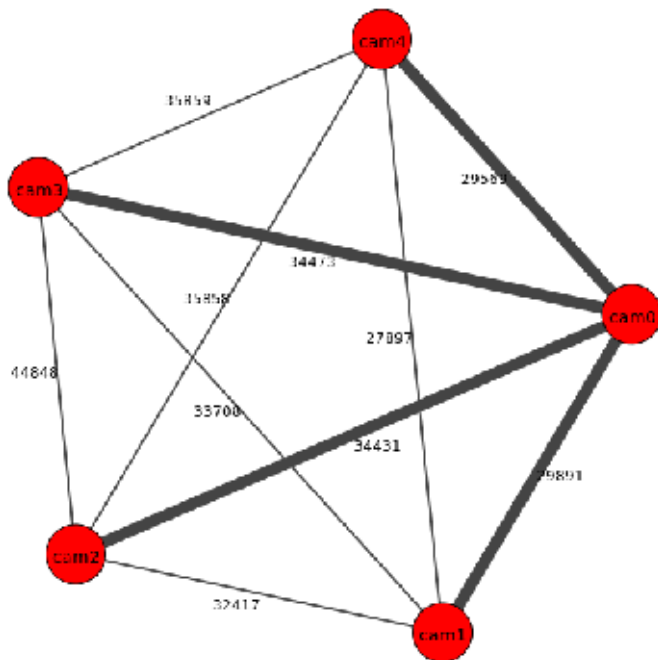
Rows: 5

Cols: 7

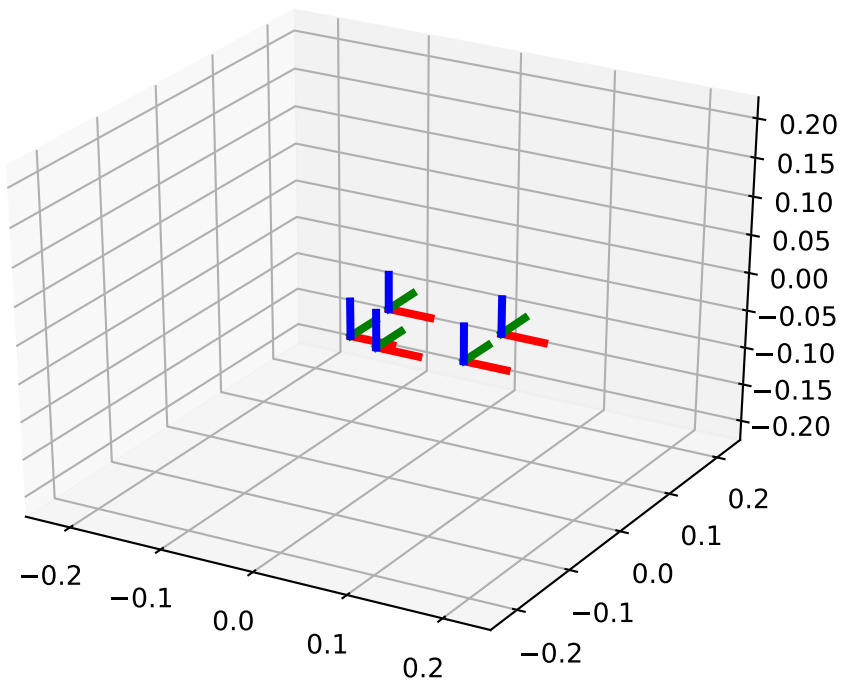
Size: 0.04 [m]

Spacing 0.01 [m]

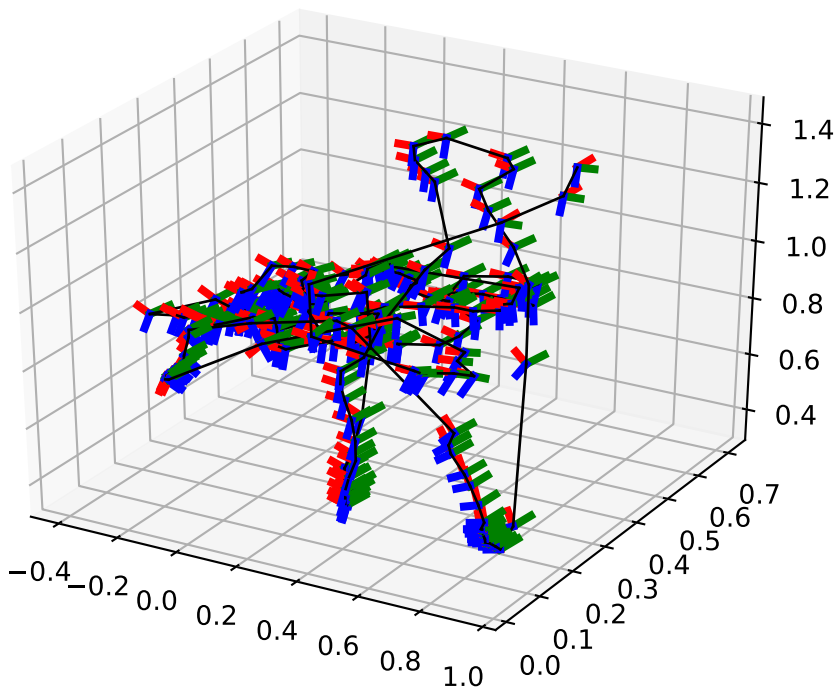
Inter-camera observations graph (edge weight=#mutual obs.)



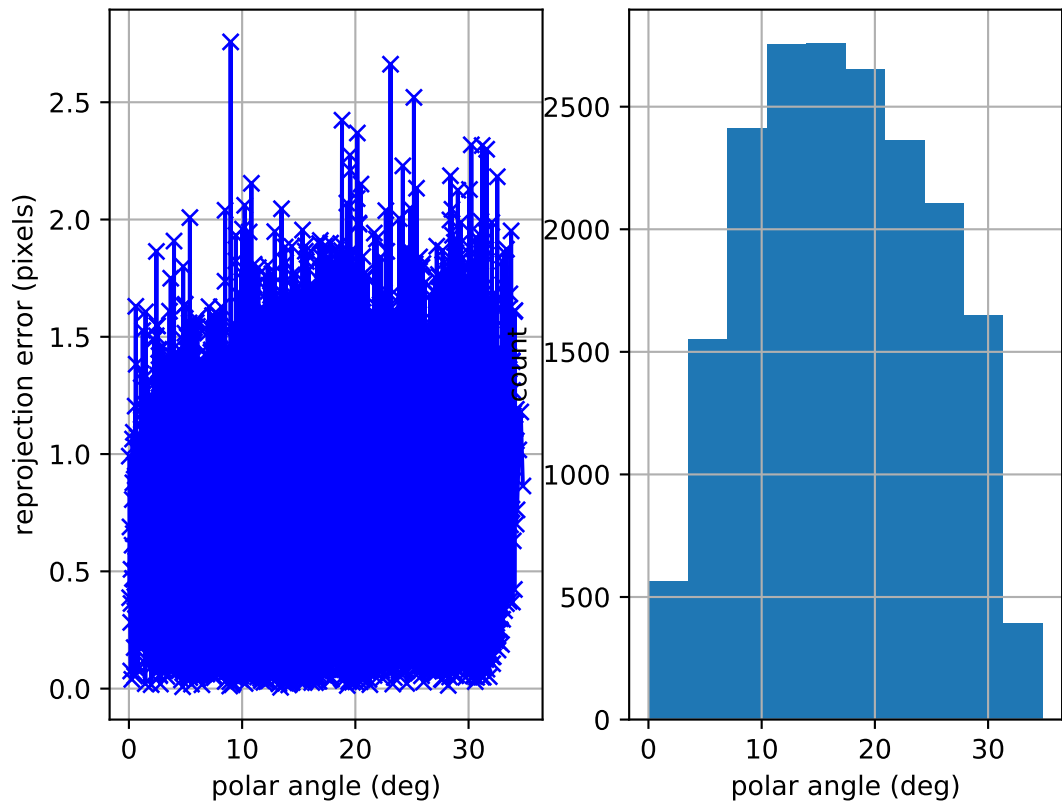
camera system



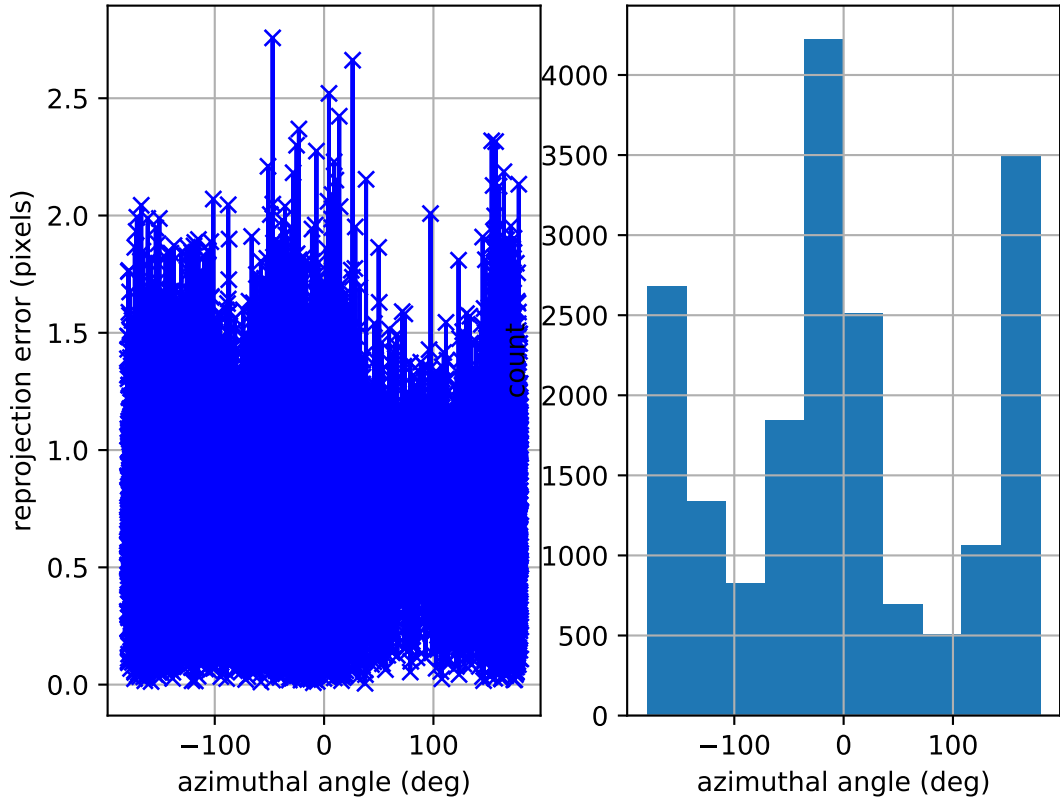
cam0: estimated poses



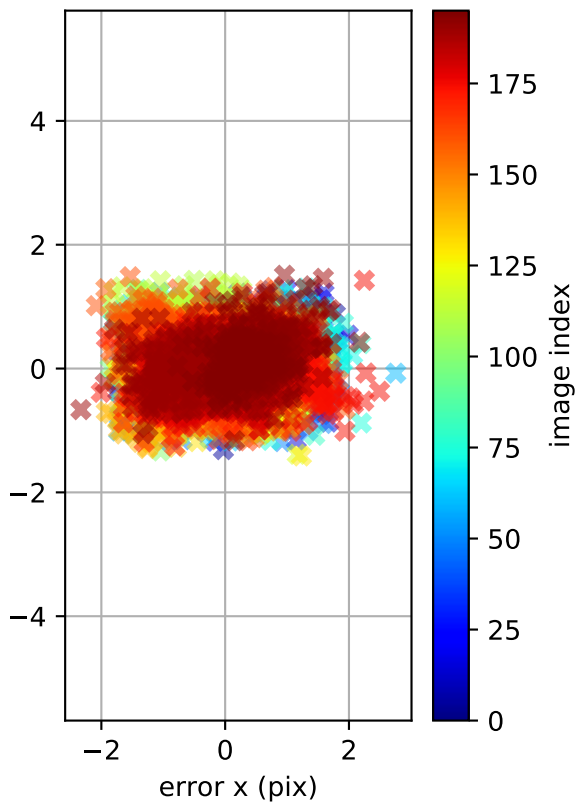
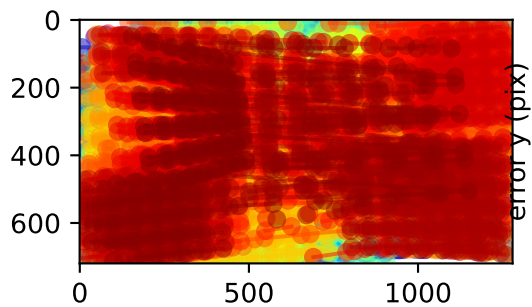
cam0: polar error



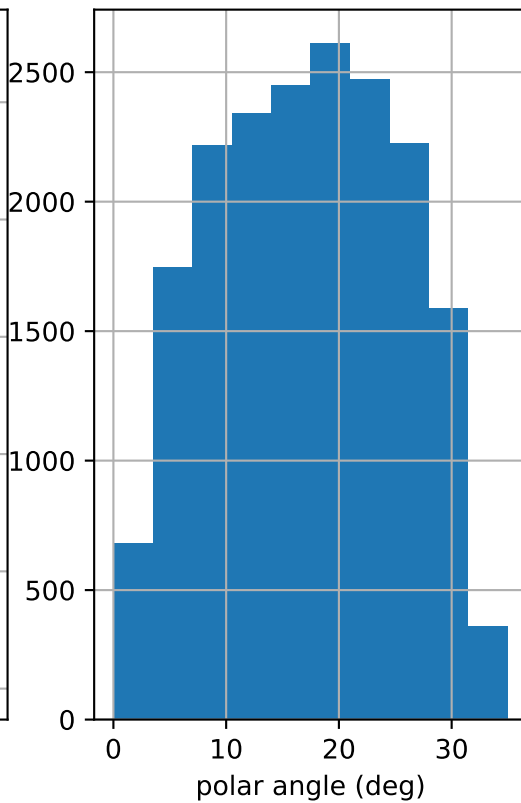
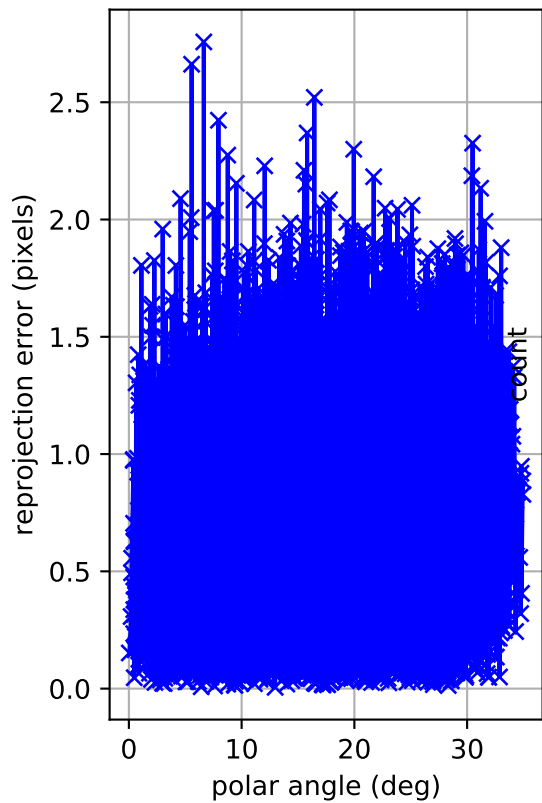
cam0: azimuthal error



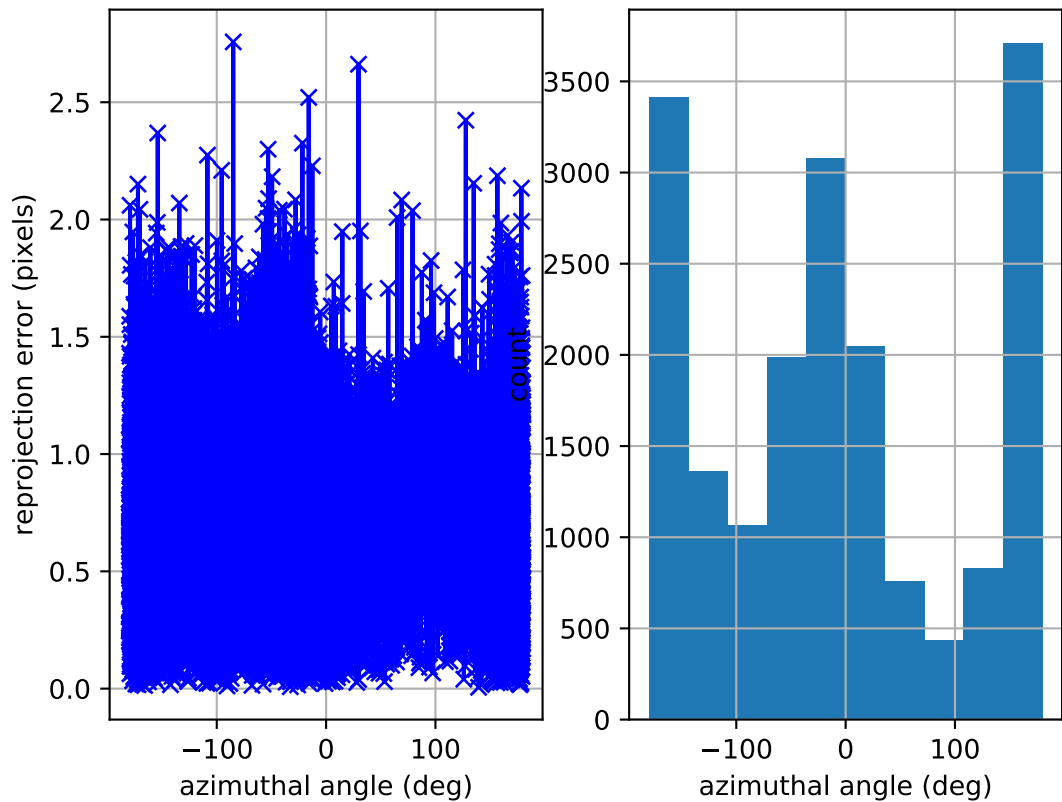
cam0: reprojection errors



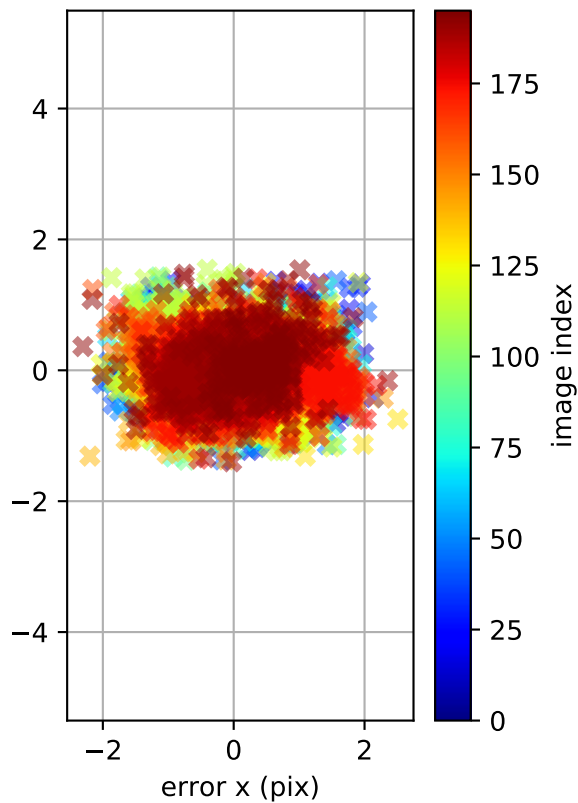
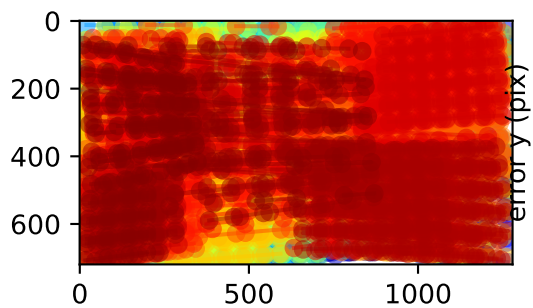
cam1: polar error



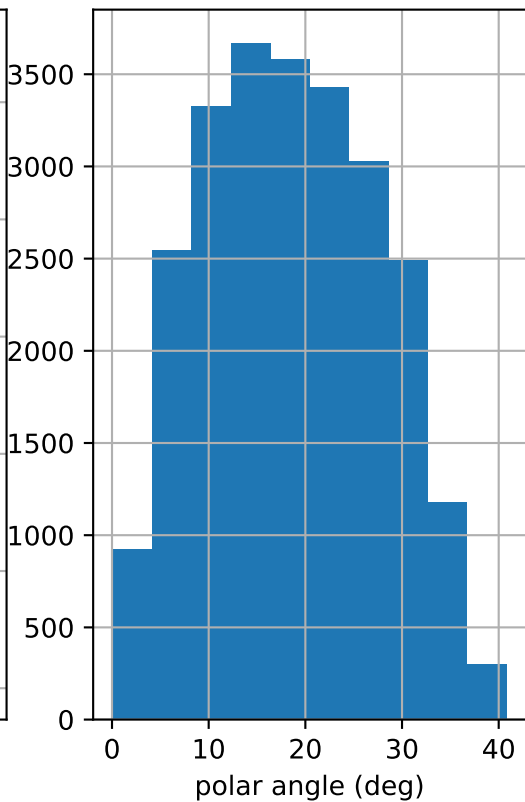
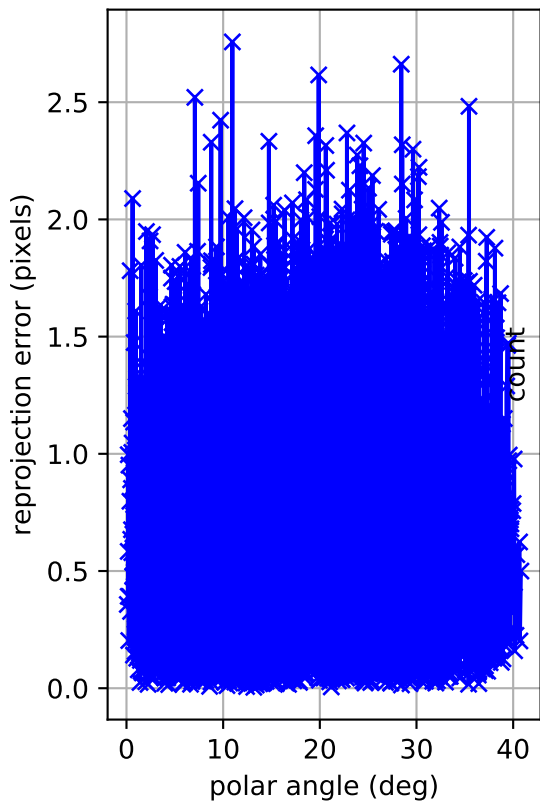
cam1: azimuthal error



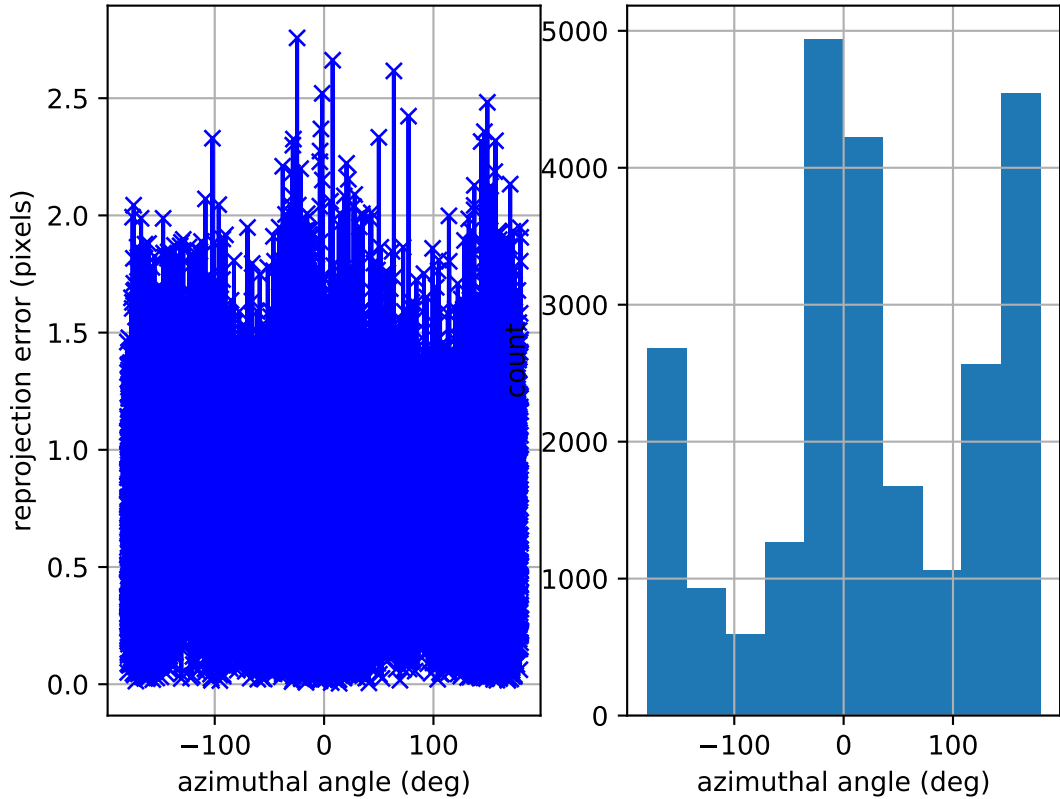
cam1: reprojection errors



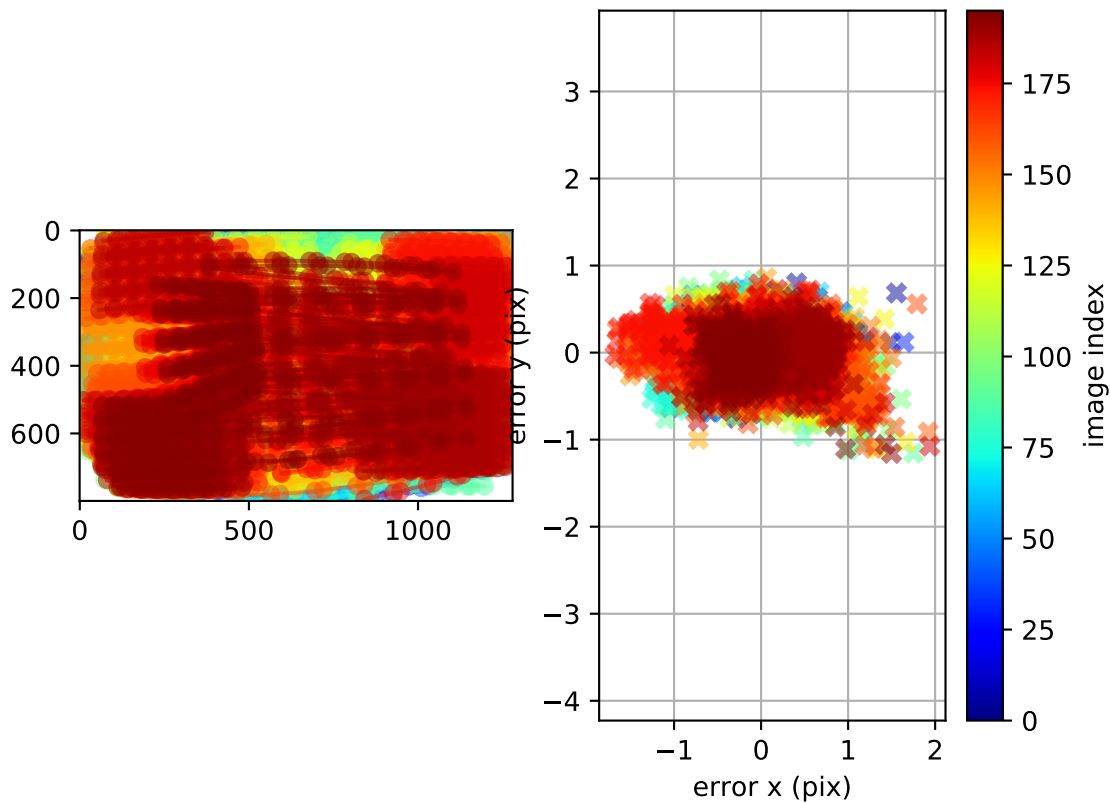
cam2: polar error



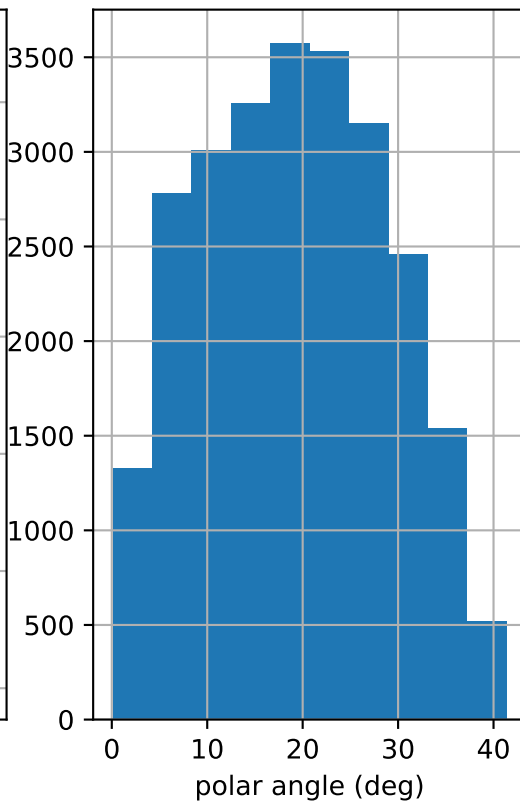
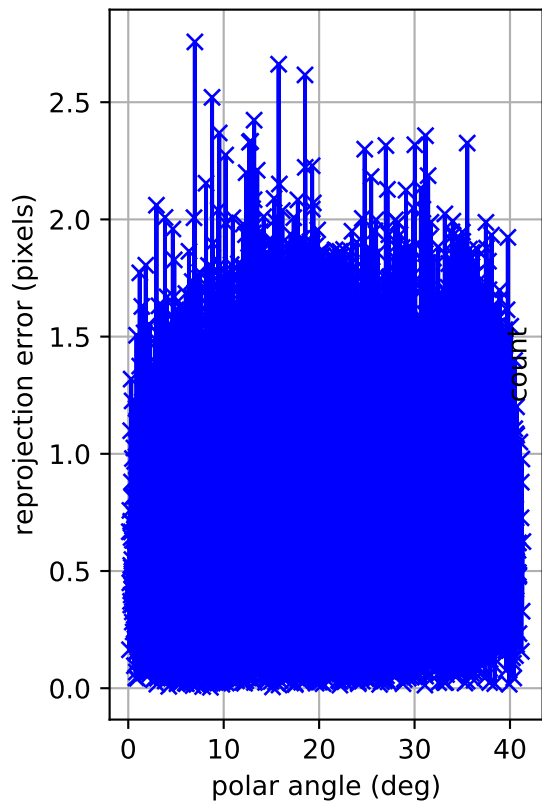
cam2: azimuthal error



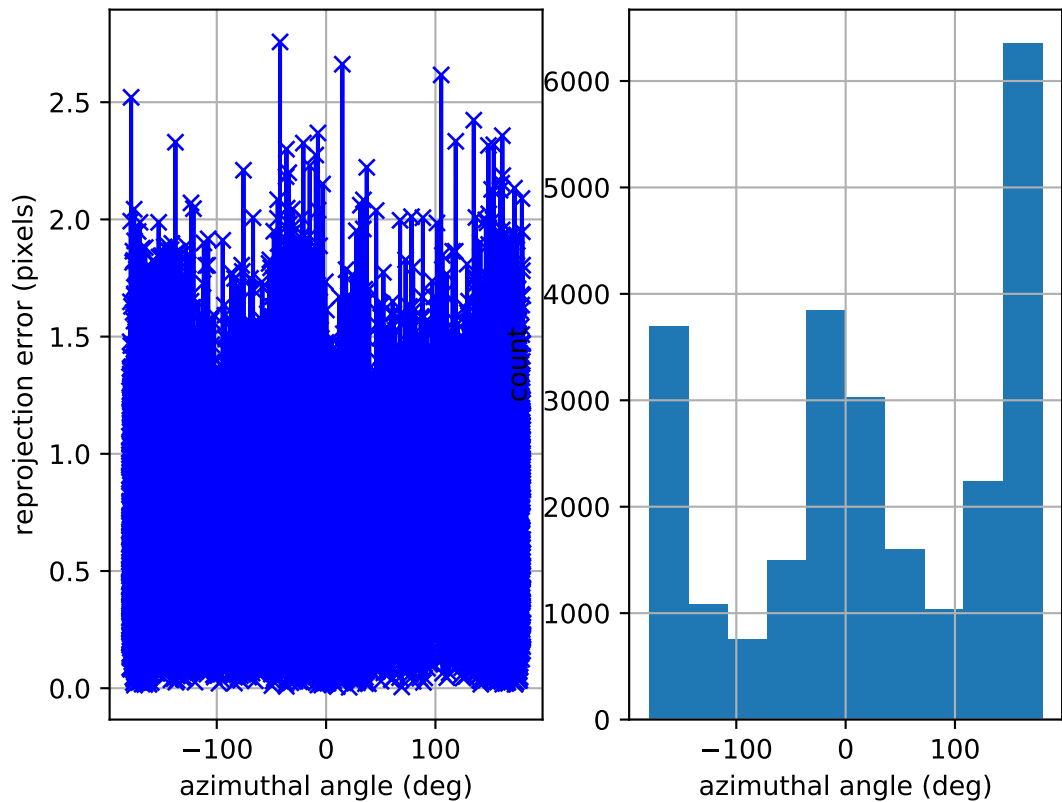
cam2: reprojection errors



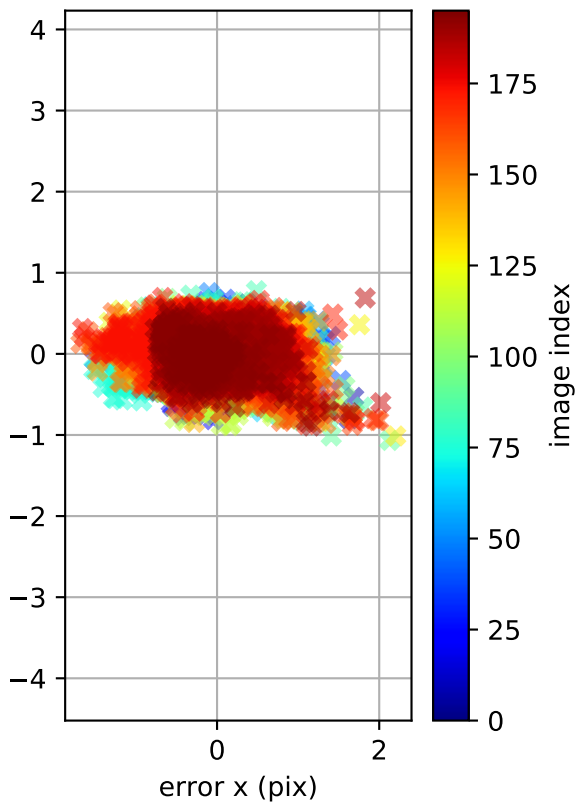
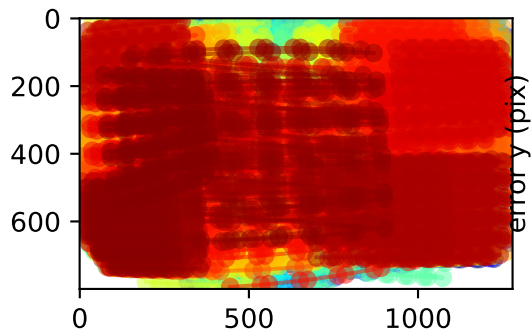
cam3: polar error



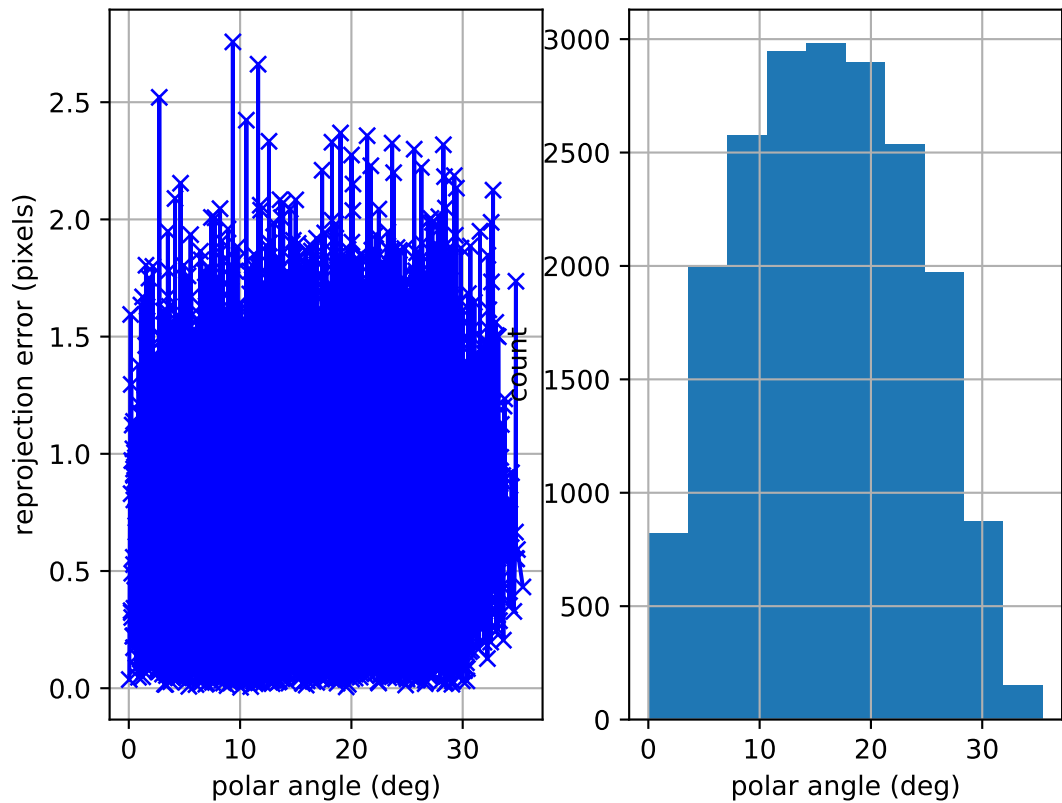
cam3: azimuthal error



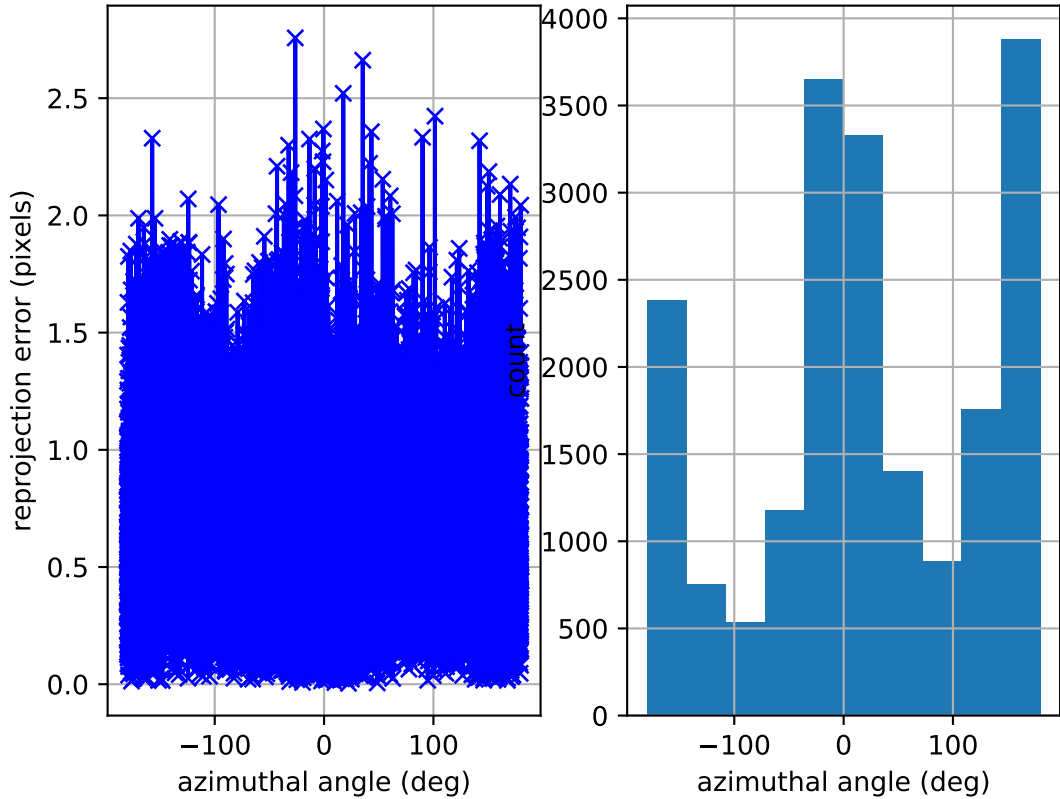
cam3: reprojection errors



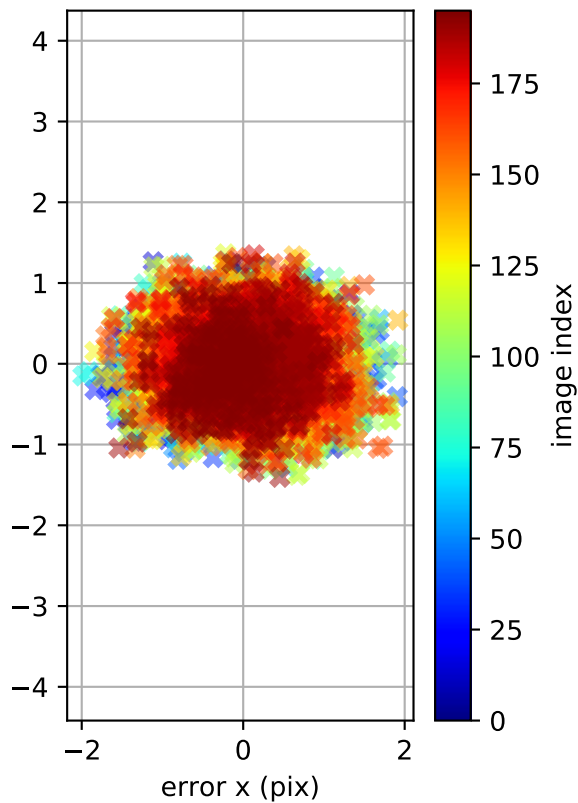
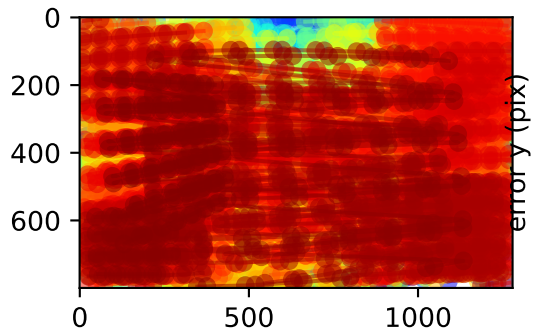
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

