

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.03648774 0.07227954 0.0006953 0.00006361] +- [0.00094417 0.00195984 0.00008156 0.00005905]

projection: [1034.39696079 1034.73607278 636.27410756 364.73952748] +- [0.13026619 0.13213605 0.02729322 0.16338287]

reprojection error: [0.000088, 0.000009] +- [0.663666, 0.391673]

cam1 (/prophesee/right/events):

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

distortion: [-0.04557034 0.07839168 0.00152212 0.00125539] +- [0.00101105 0.00221065 0.00007236 0.00005681]

projection: [1034.61302587 1034.83604567 638.12992827 366.88002829] +- [0.1302985 0.1278338 0.00567424 0.04878974]

reprojection error: [0.000087, -0.000025] +- [0.644019, 0.397439]

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

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

distortion: [-0.39302515 0.15568976 -0.00034827 0.00040482] +- [0.0004912 0.00080301 0.00004744 0.0000368]

projection: [1060.9212873 1060.80047152 673.20501251 338.69126206] +- [0.11583664 0.11812346 0.01724906 0.15544996]

reprojection error: [0.000153, -0.000277] +- [0.387787, 0.227729]

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

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

distortion: [-0.39084134 0.14891329 -0.0006863 0.0011008] +- [0.00042998 0.00063442 0.00004763 0.00003564]

projection: [1055.83693309 1056.21141254 670.9513347 331.83778279] +- [0.11080806 0.11183083 0.02565251 0.16423977]

reprojection error: [0.000118, -0.000389] +- [0.386379, 0.221373]

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

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

distortion: [-0.41333594 0.18090805 -0.00002799 -0.00003785] +- [0.00075876 0.00174582 0.00005475 0.00004117]

projection: [1269.24837363 1269.16020362 650.94892772 368.38236713] +- [0.13013716 0.13013354 0.00794407 0.03613636]

reprojection error: [0.000031, 0.000156] +- [0.463241, 0.361881]

baseline T_1_0:

q: [0.00006839 0.00175513 -0.00033319 0.9999984] +- [0.00016805 0.00005486 0.00003368]

t: [-0.1201794 0.00091033 -0.00043059] +- [0.00003719 0.00003538 0.0001153]

baseline T_2_1:

q: [-0.00064548 -0.00578264 -0.00445913 0.99997313] +- [0.00015042 0.00004652 0.00003273]

t: [0.11984202 0.06918972 0.00333159] +- [0.00003559 0.00003316 0.00011354]

baseline T_3_2:

q: [-0.00035866 0.00084736 0.00028377 0.99999954] +- [0.00025136 0.00005346 0.00002775]

t: [-0.1201081 -0.00009281 0.00079712] +- [0.00003422 0.00003027 0.00010847]

baseline T_4_3:

q: [0.00324694 0.00153361 0.00034402 0.99999349] +- [0.00017482 0.00004793 0.00002835]

t: [0.08897331 0.00608356 0.00313733] +- [0.00003116 0.00002872 0.00010598]

Target configuration

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Type: aprilgrid

Tags:

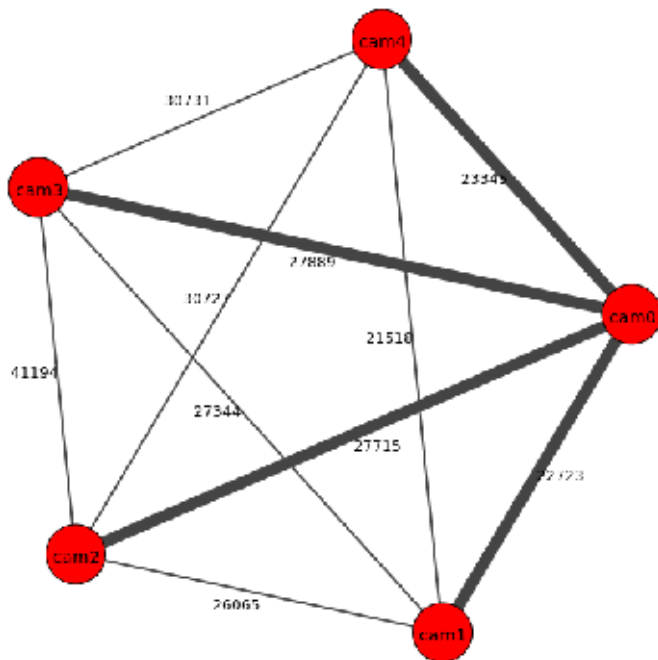
Rows: 5

Cols: 7

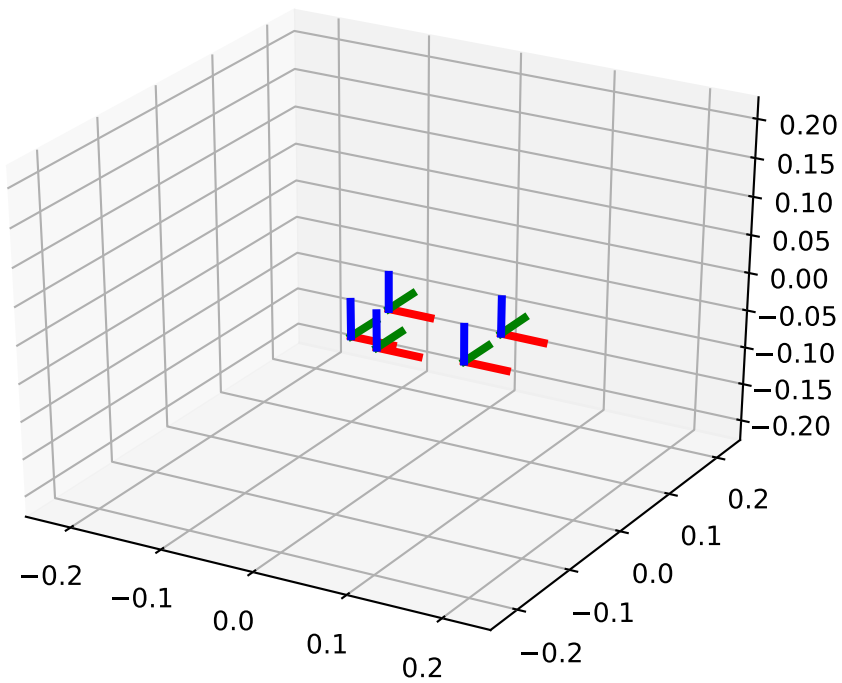
Size: 0.04 [m]

Spacing 0.01 [m]

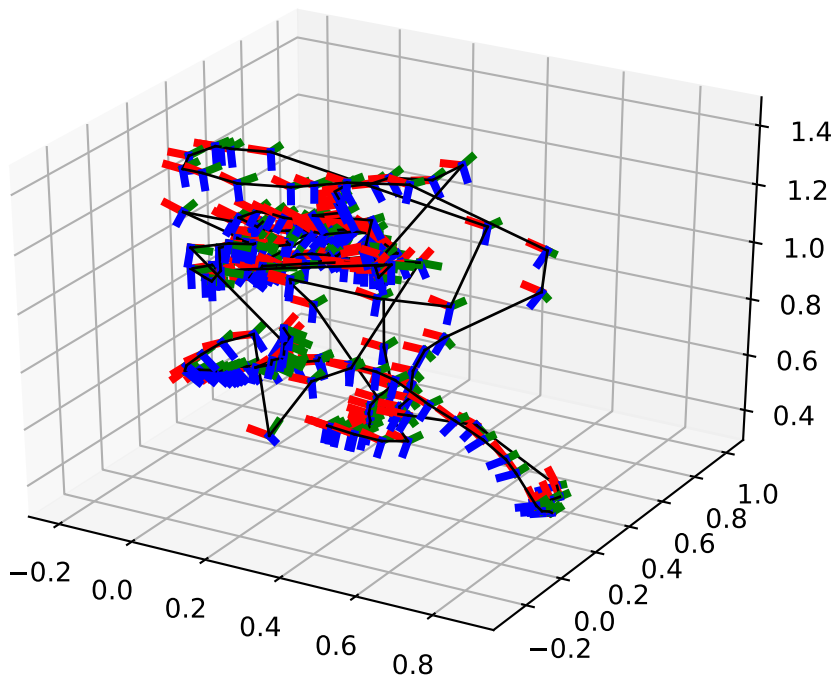
Inter-camera observations graph (edge weight=#mutual obs.)



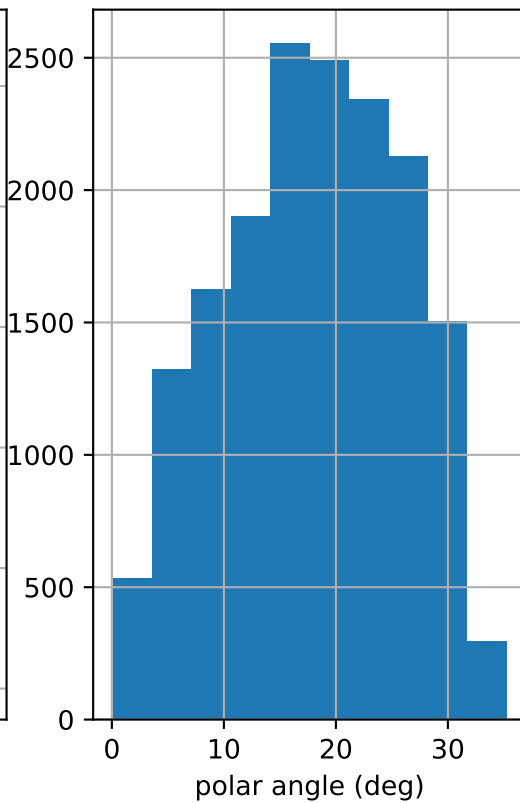
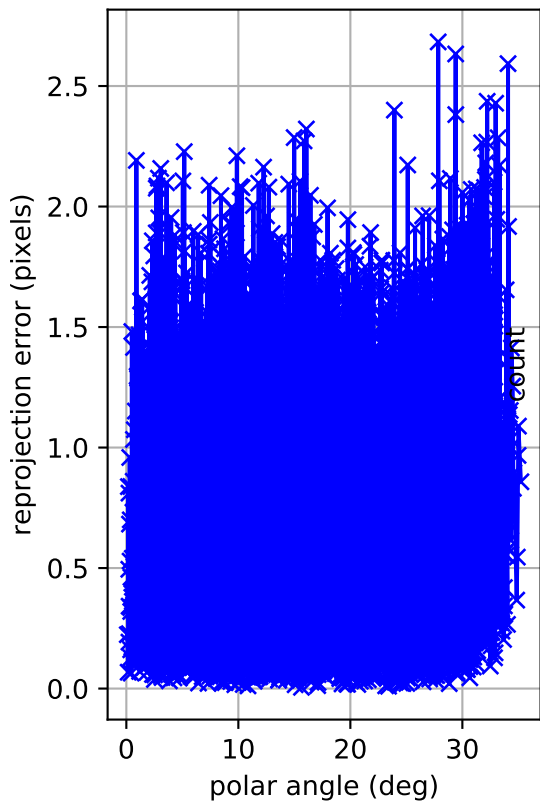
camera system



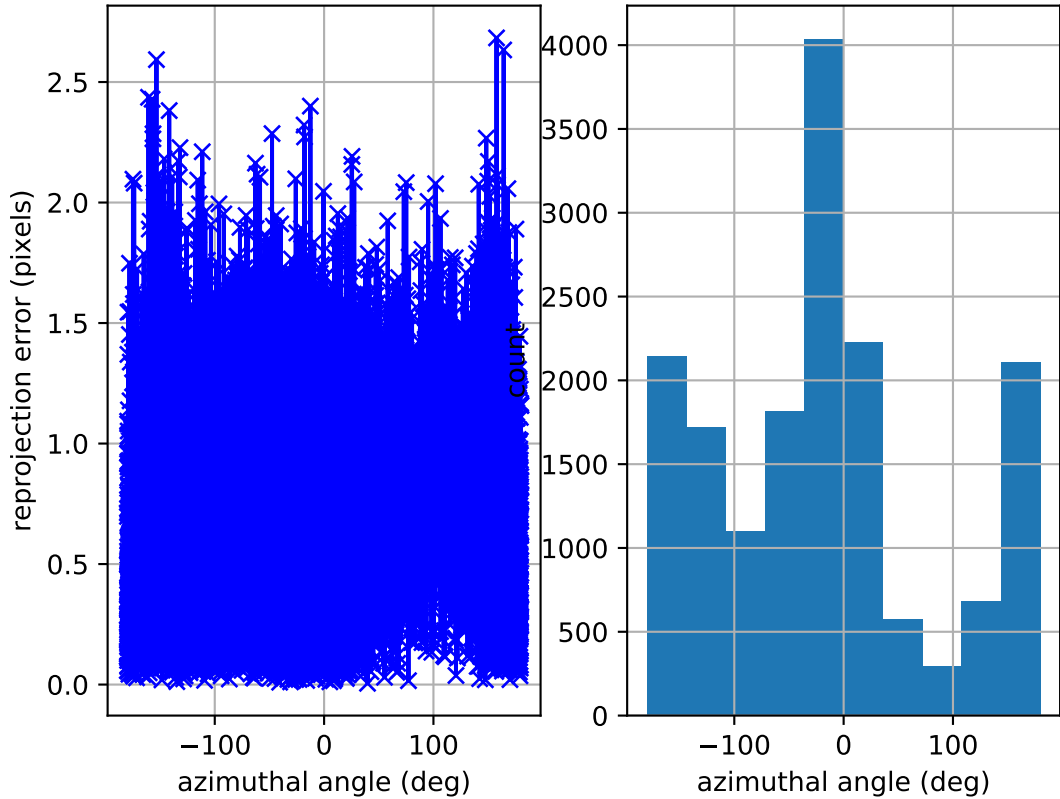
cam0: estimated poses



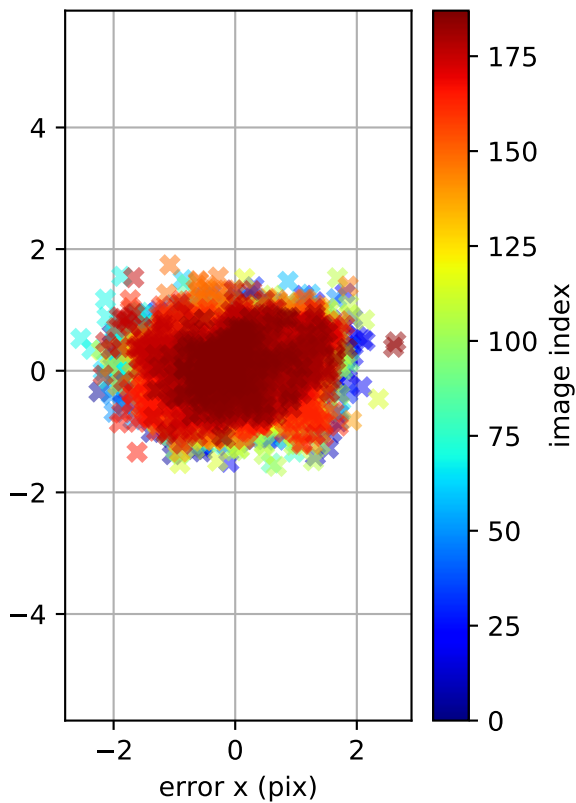
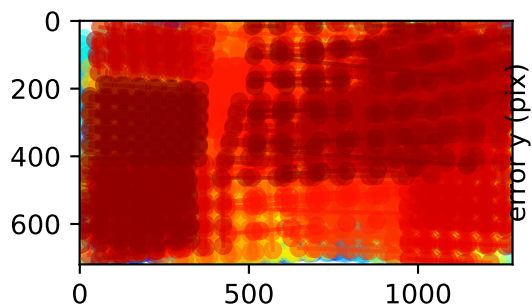
cam0: polar error



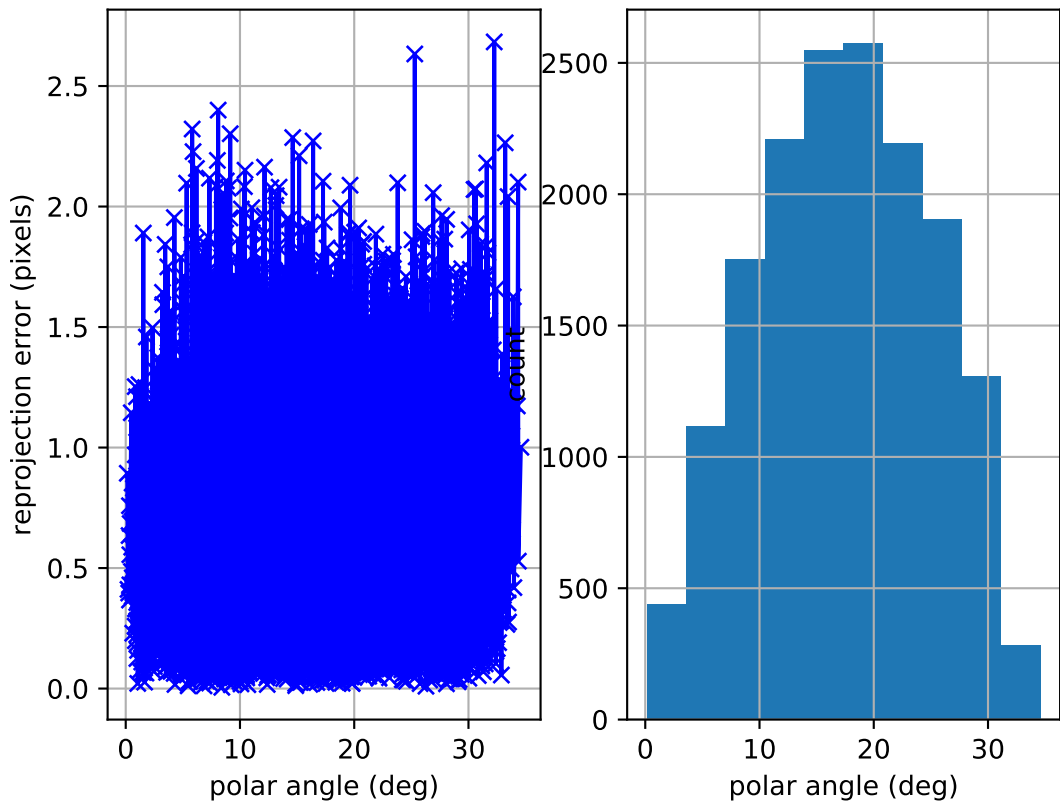
cam0: azimuthal error



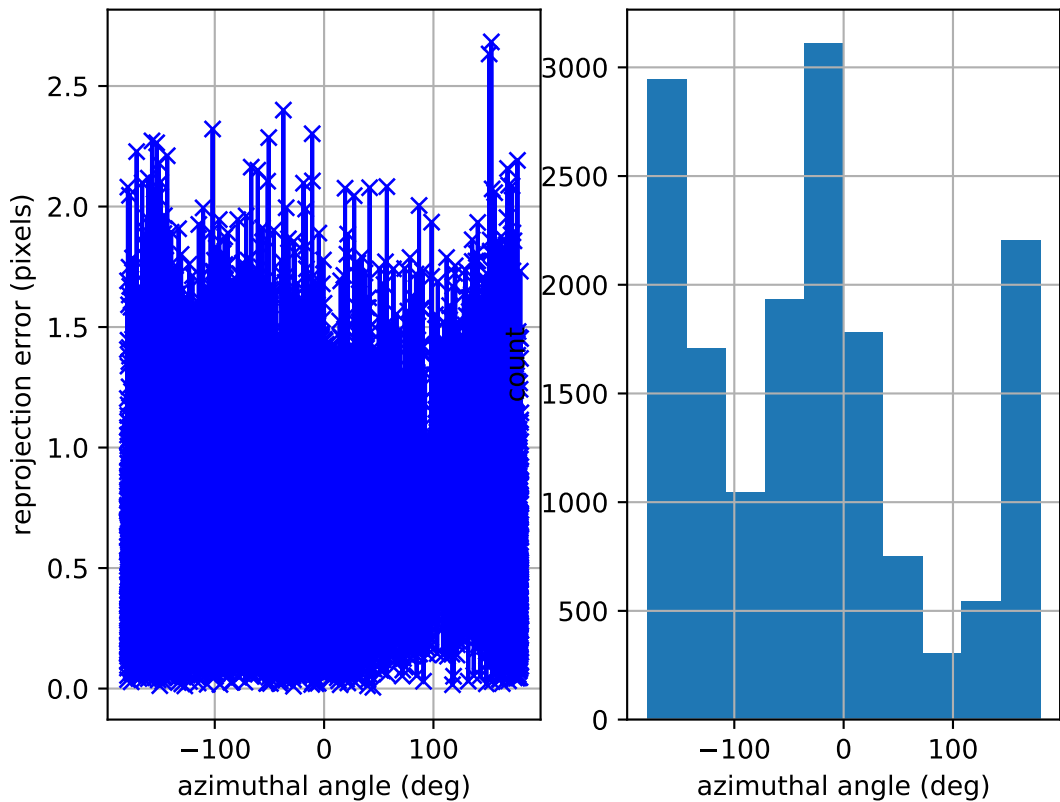
cam0: reprojection errors



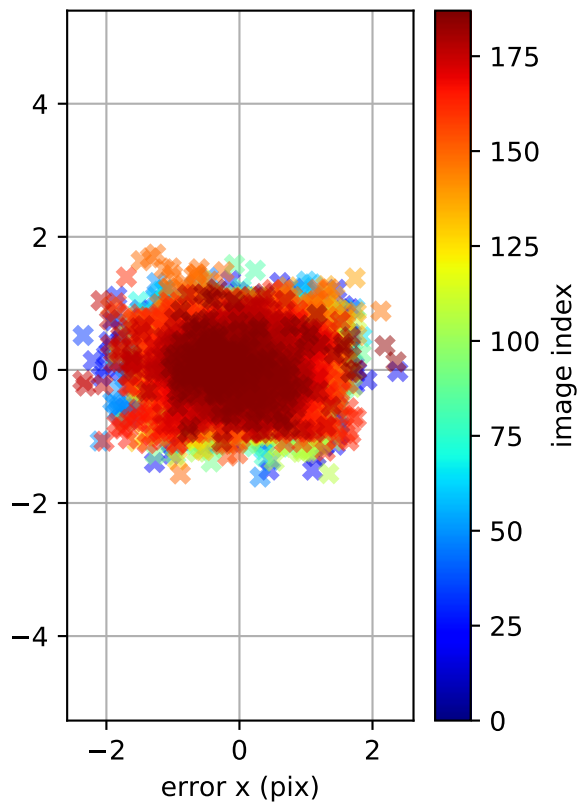
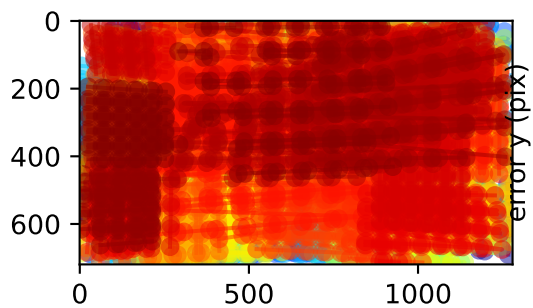
cam1: polar error



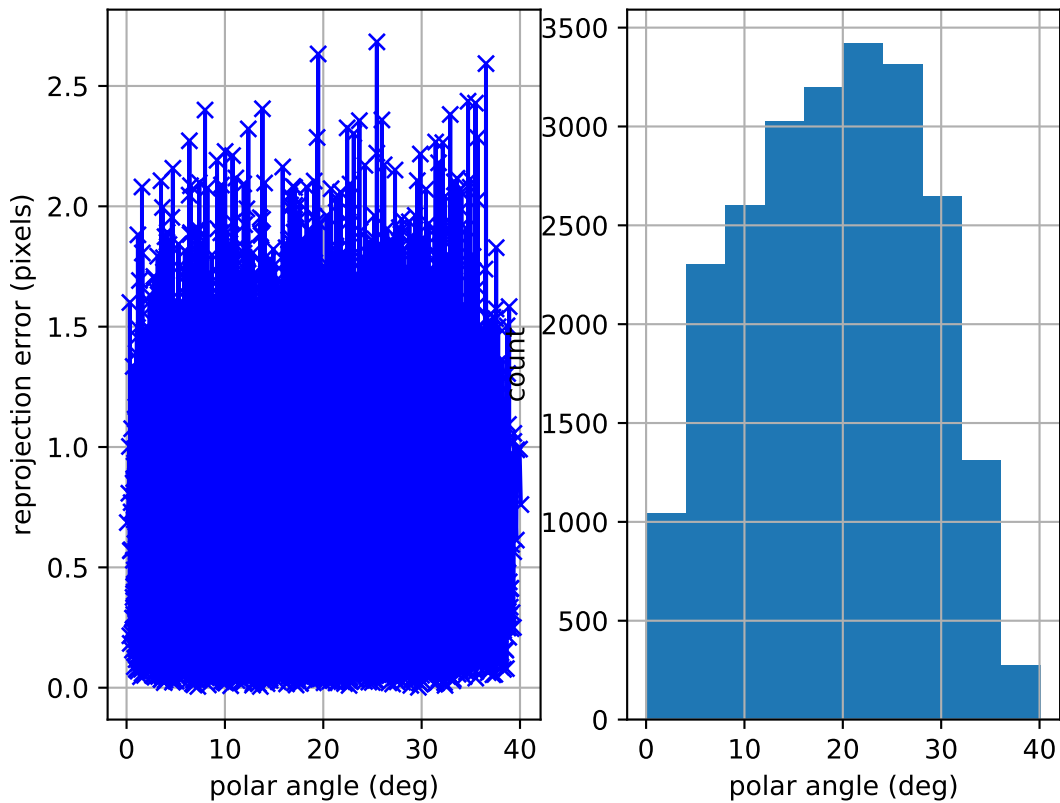
cam1: azimuthal error



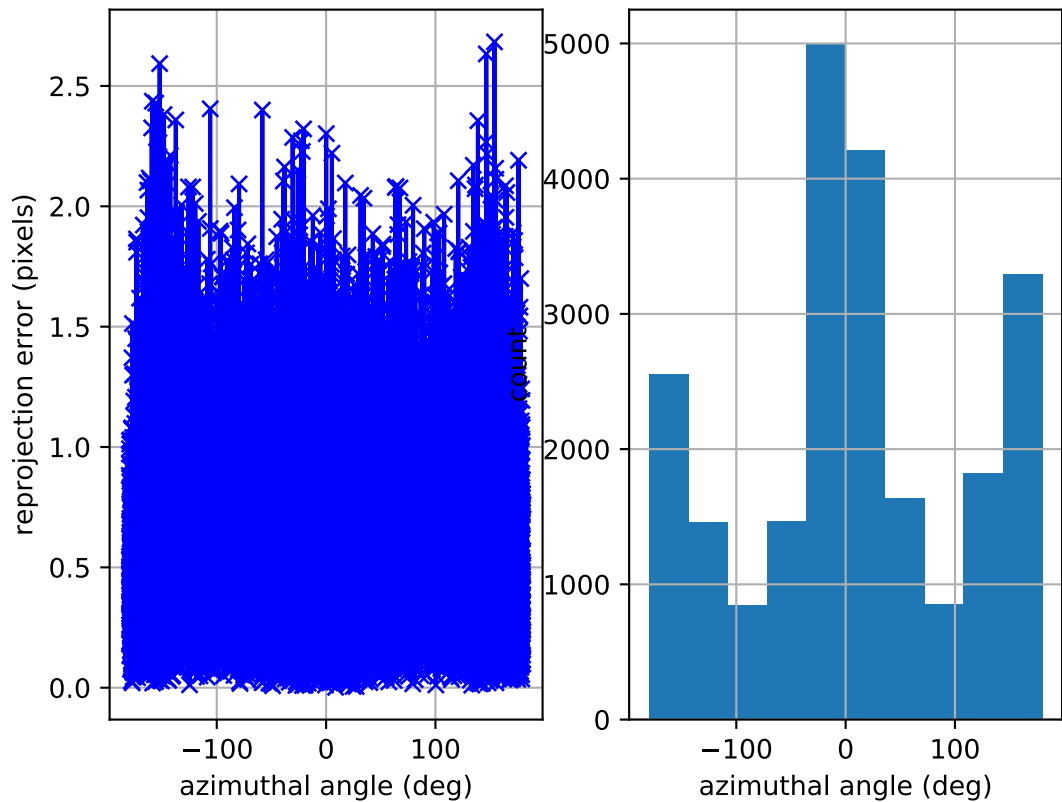
cam1: reprojection errors



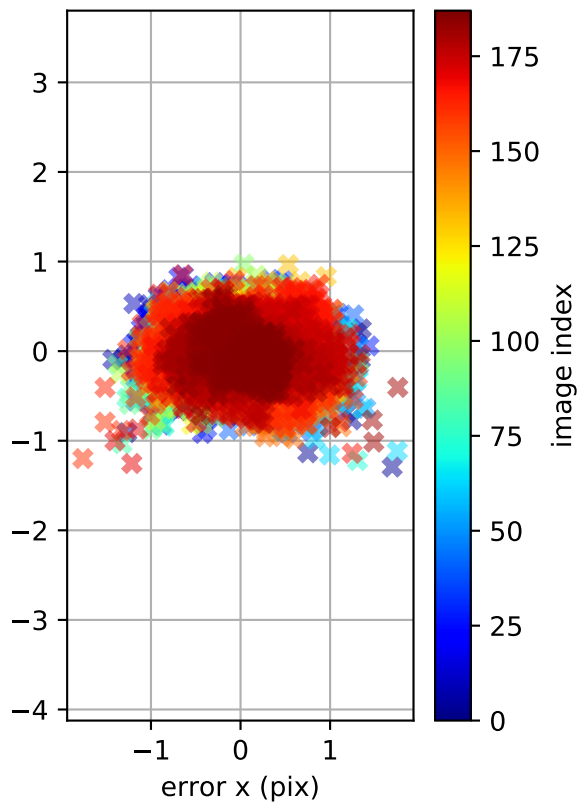
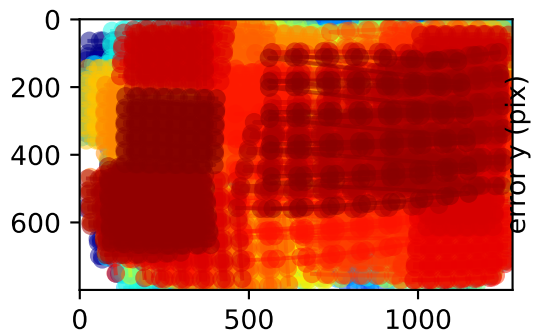
cam2: polar error



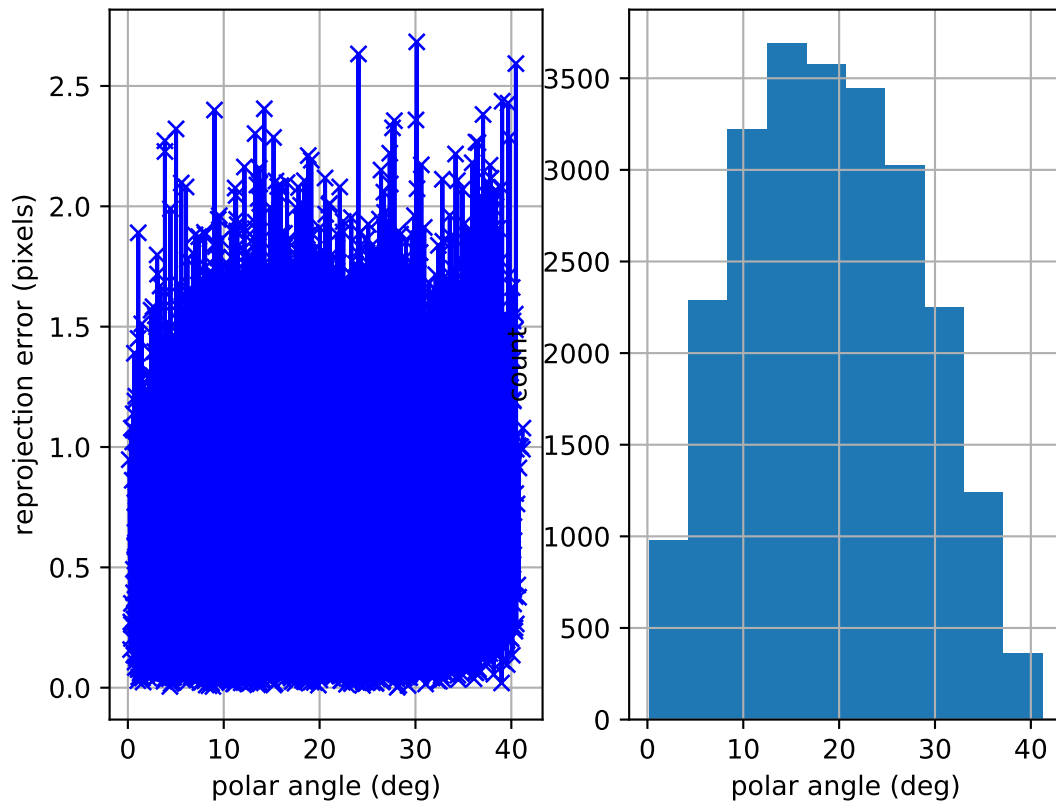
cam2: azimuthal error



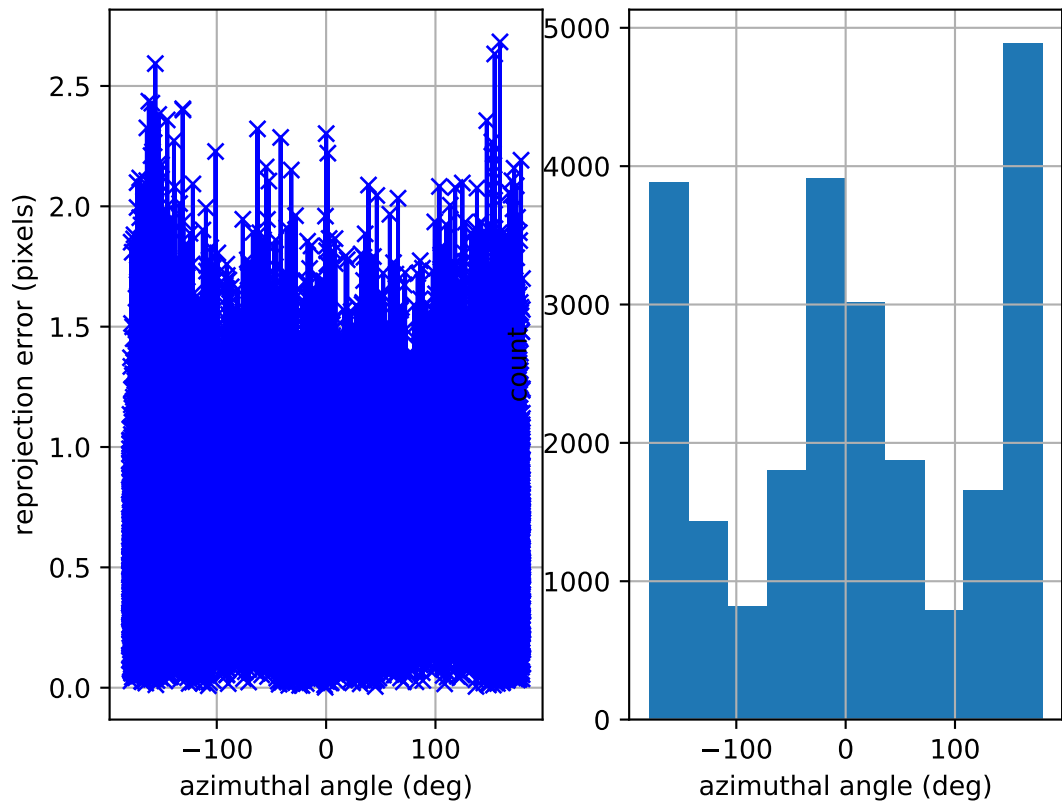
cam2: reprojection errors



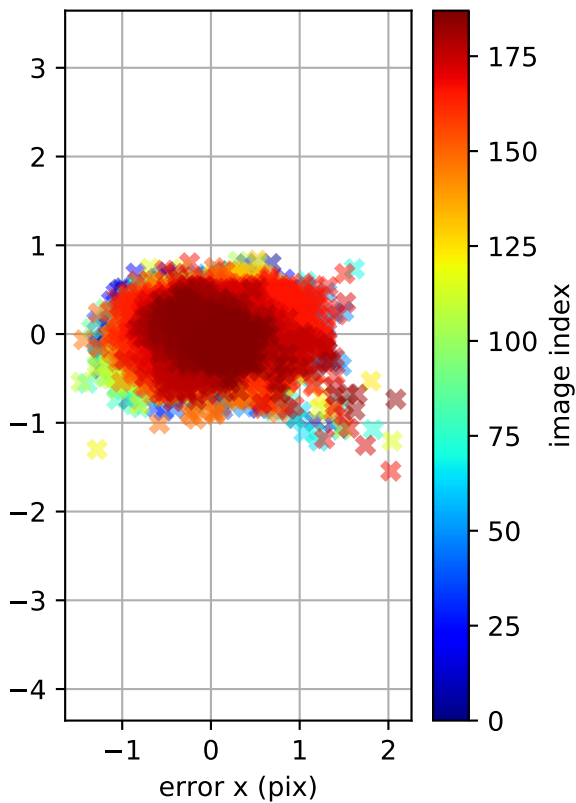
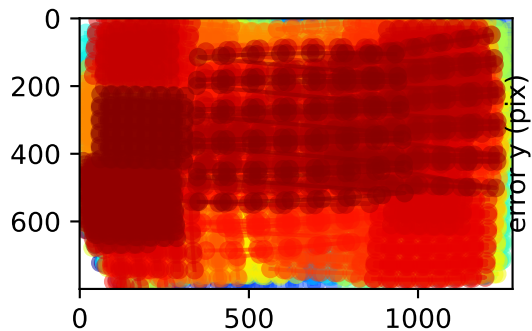
cam3: polar error



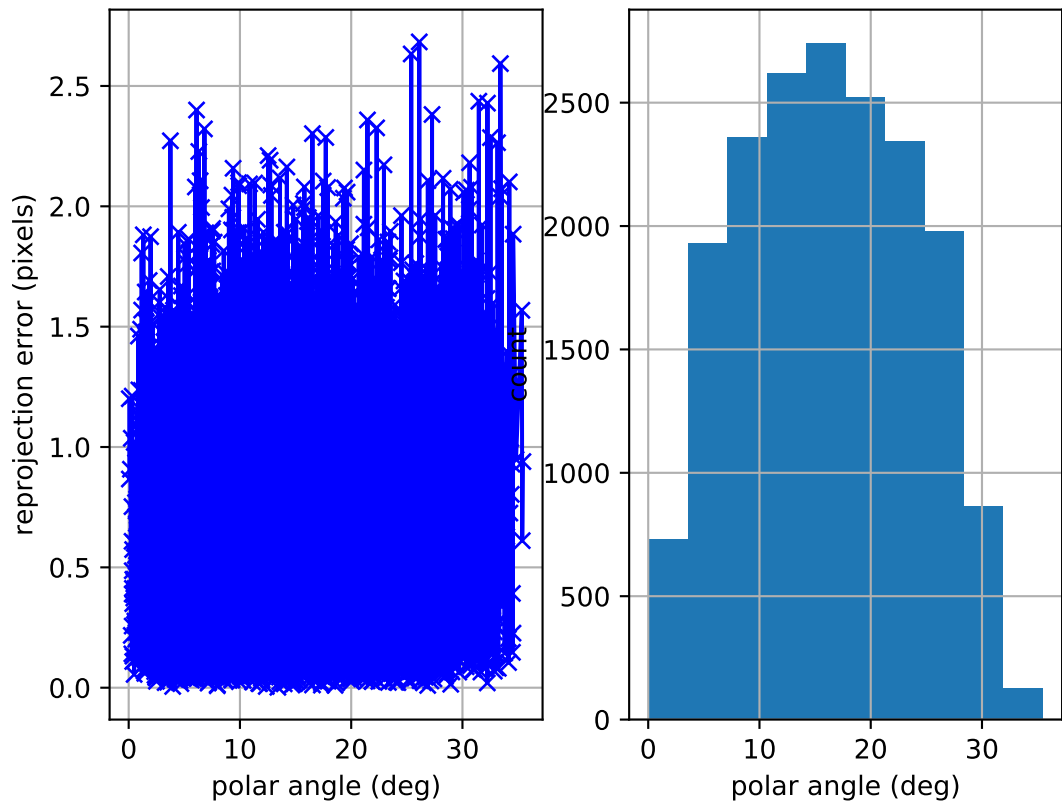
cam3: azimuthal error



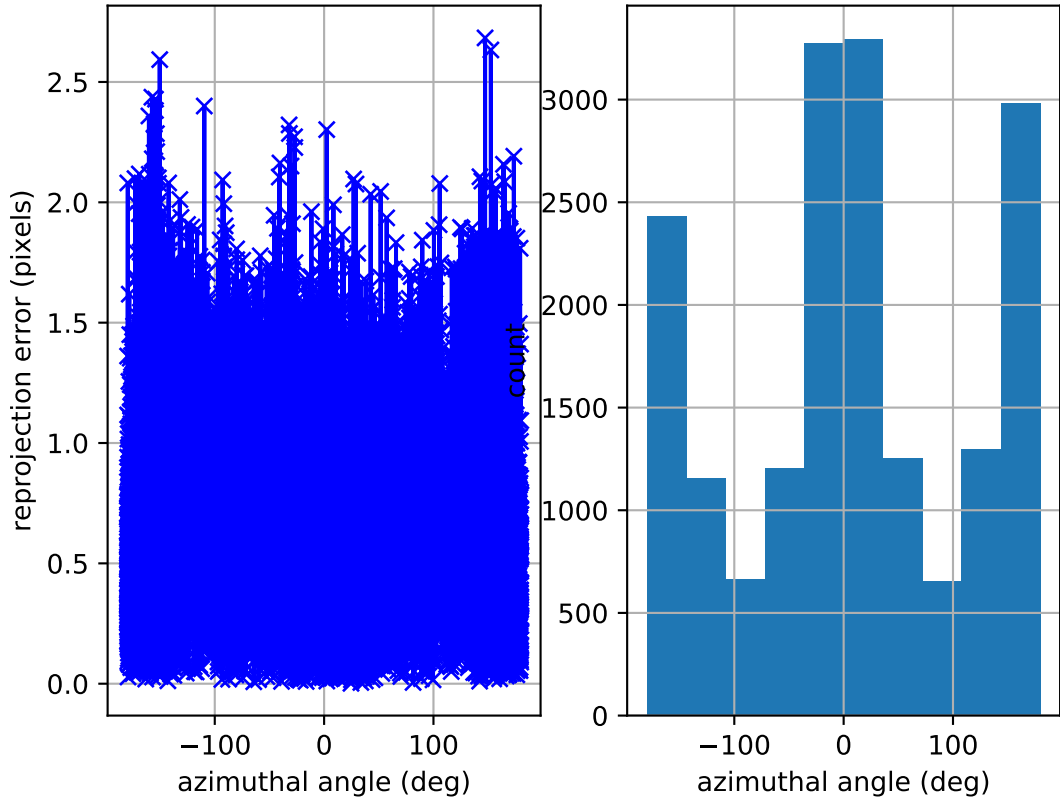
cam3: reprojection errors



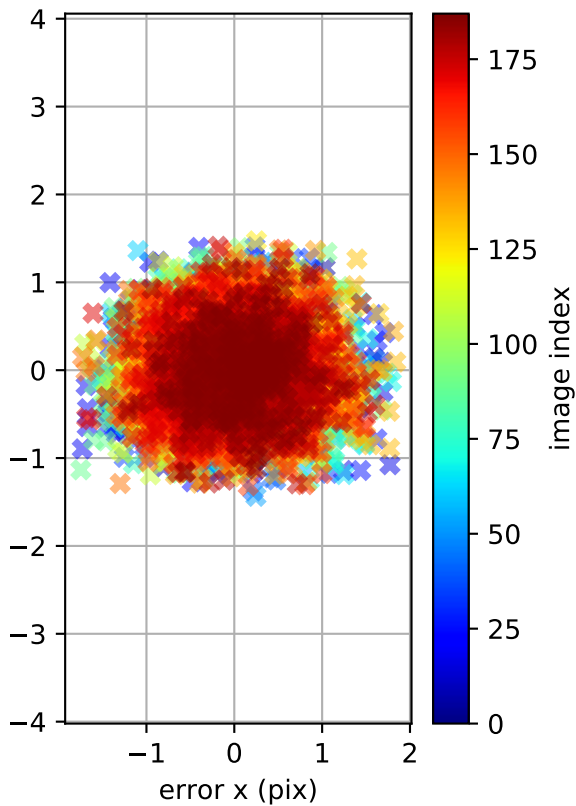
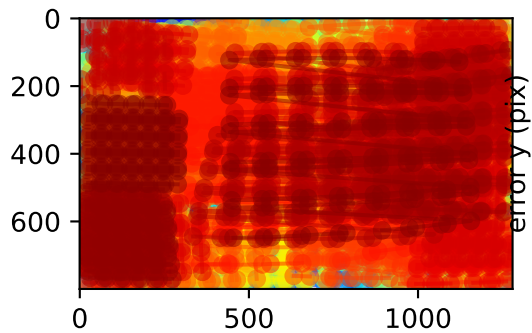
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

