

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04512417 0.07964441 0.00088282 -0.00188746] +- [0.00103468 0.00204614 0.00011458 0.00008033]

projection: [1032.96138833 1032.8263147 632.38290823 368.57212974] +- [0.12883756 0.14179352 0.0188061 0.14918888]

reprojection error: [0.000004, -0.000083] +- [0.365700, 0.347291]

cam1 (/prophesee/right/events):

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

distortion: [-0.04921083 0.07831975 0.00197272 -0.00088872] +- [0.00102011 0.00203056 0.00011481 0.00008066]

projection: [1032.26867081 1032.57448492 632.85489859 370.0490076] +- [0.12894556 0.1413507 0.01262151 0.14002356]

reprojection error: [-0.000022, -0.000069] +- [0.432516, 0.413215]

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

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

distortion: [-0.39348399 0.15751421 -0.00037661 0.00061553] +- [0.00059837 0.00097443 0.00007422 0.00004936]

projection: [1058.26520352 1058.49243286 673.42808987 337.91643305] +- [0.13033515 0.12987245 0.01593046 0.19595576]

reprojection error: [0.000131, -0.000097] +- [0.200128, 0.171382]

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

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

distortion: [-0.39166569 0.1507151 -0.00052075 0.00119373] +- [0.00053211 0.00076491 0.0000736 0.00004973]

projection: [1053.12162947 1053.72117453 671.16662029 330.74909932] +- [0.13257477 0.13318922 0.02918939 0.19227637]

reprojection error: [0.000266, -0.000138] +- [0.214538, 0.175125]

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

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

distortion: [-0.41422259 0.18270239 -0.00028372 0.00021536] +- [0.00083491 0.00182285 0.00007979 0.00005397]

projection: [1264.95812914 1264.98650426 650.66251521 370.67362908] +- [0.14336417 0.14436678 0.01890631 0.09101722]

reprojection error: [0.000139, -0.000130] +- [0.238881, 0.235886]

baseline T_1_0:

q: [-0.00102528 0.00186209 -0.0003497 0.99999768] +- [0.0002211 0.00006452 0.00004203]

t: [-0.12013768 0.00103034 0.00046669] +- [0.00004623 0.00004522 0.00011824]

baseline T_2_1:

q: [-0.00014659 -0.00189429 -0.00513507 0.99998501] +- [0.00027754 0.00005701 0.00004012]

t: [0.11997377 0.06906854 0.00319349] +- [0.00004088 0.0000388 0.00012455]

baseline T_3_2:

q: [0.00017232 -0.00246299 0.00022864 0.99999693] +- [0.00027991 0.00006132 0.00003258]

t: [-0.12006288 -0.00007692 0.00115299] +- [0.00003488 0.00003107 0.00011509]

baseline T_4_3:

q: [0.00162148 0.0048474 0.00040201 0.99998686] +- [0.00024101 0.00005783 0.00003205]

t: [0.08891194 0.00614164 0.00335233] +- [0.00003155 0.00002895 0.00011325]

Target configuration

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Type: aprilgrid

Tags:

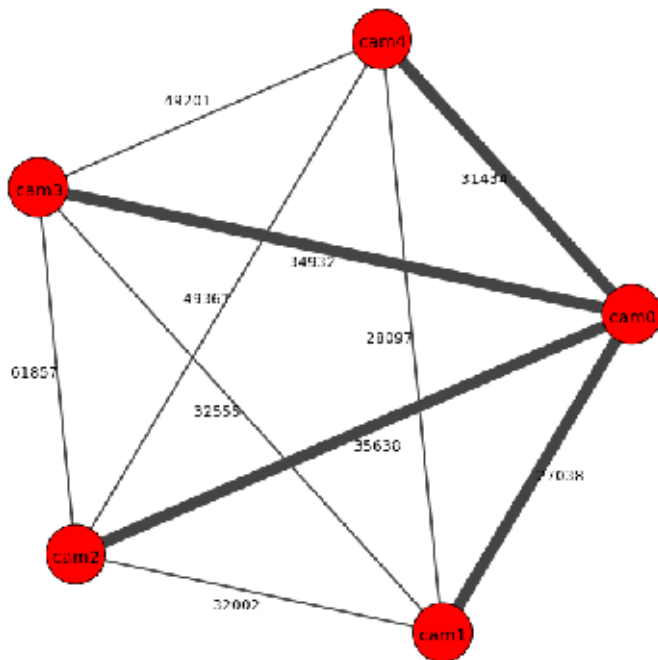
Rows: 5

Cols: 7

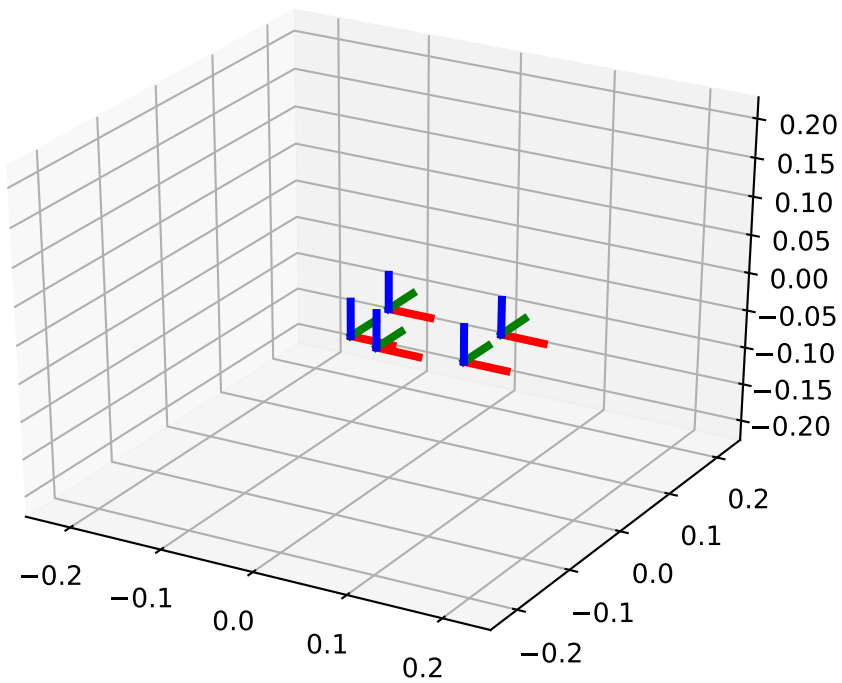
Size: 0.04 [m]

Spacing 0.01 [m]

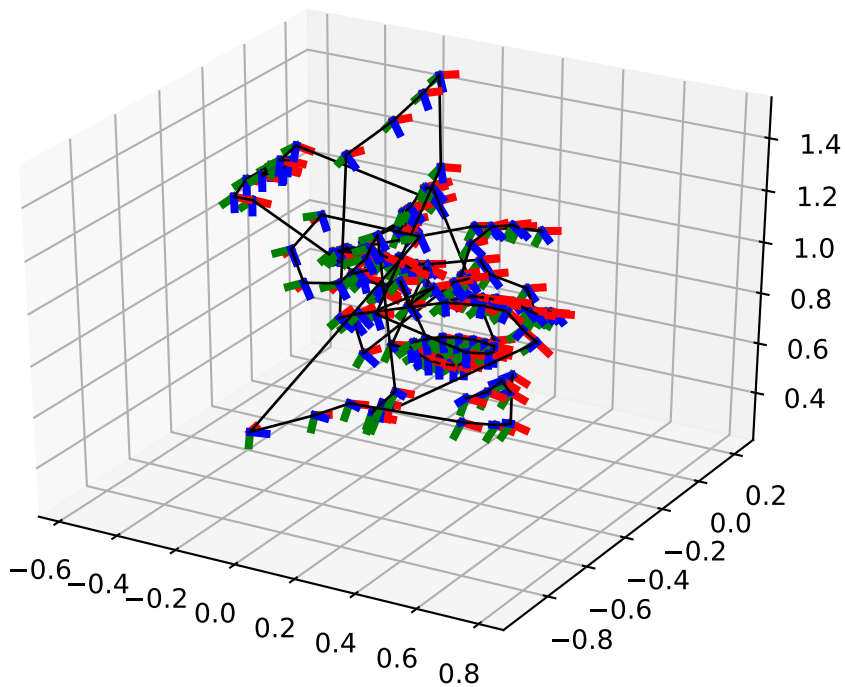
Inter-camera observations graph (edge weight=#mutual obs.)



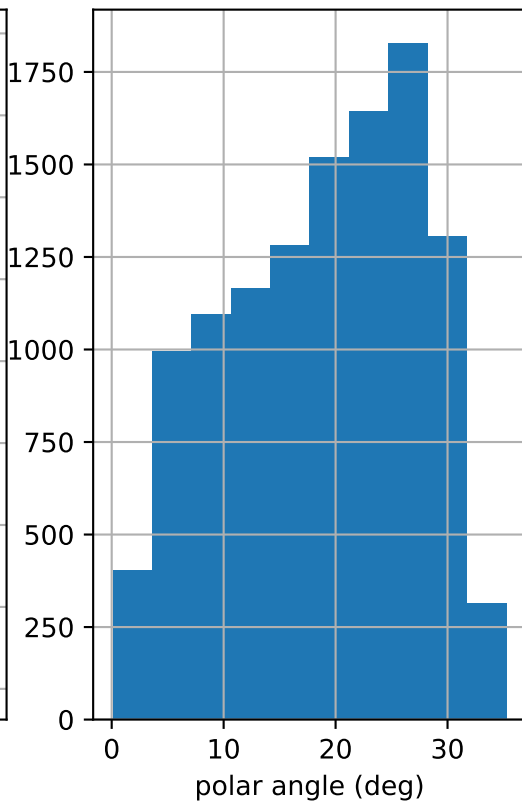
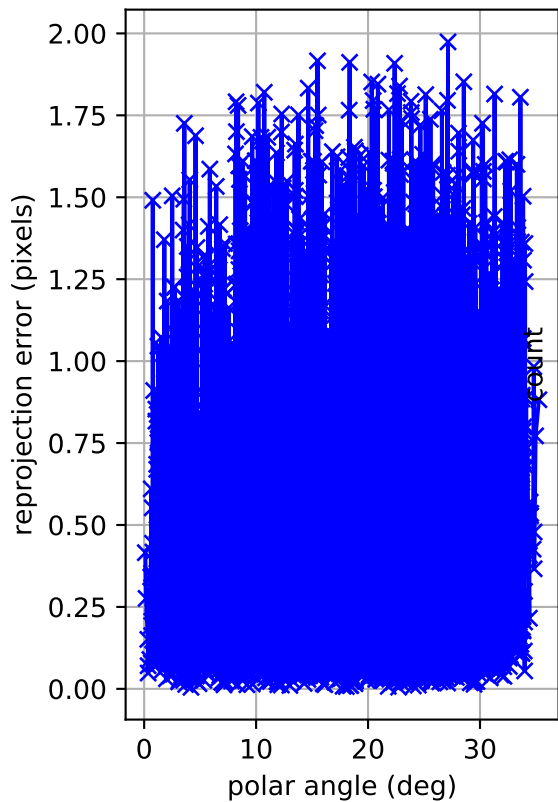
camera system



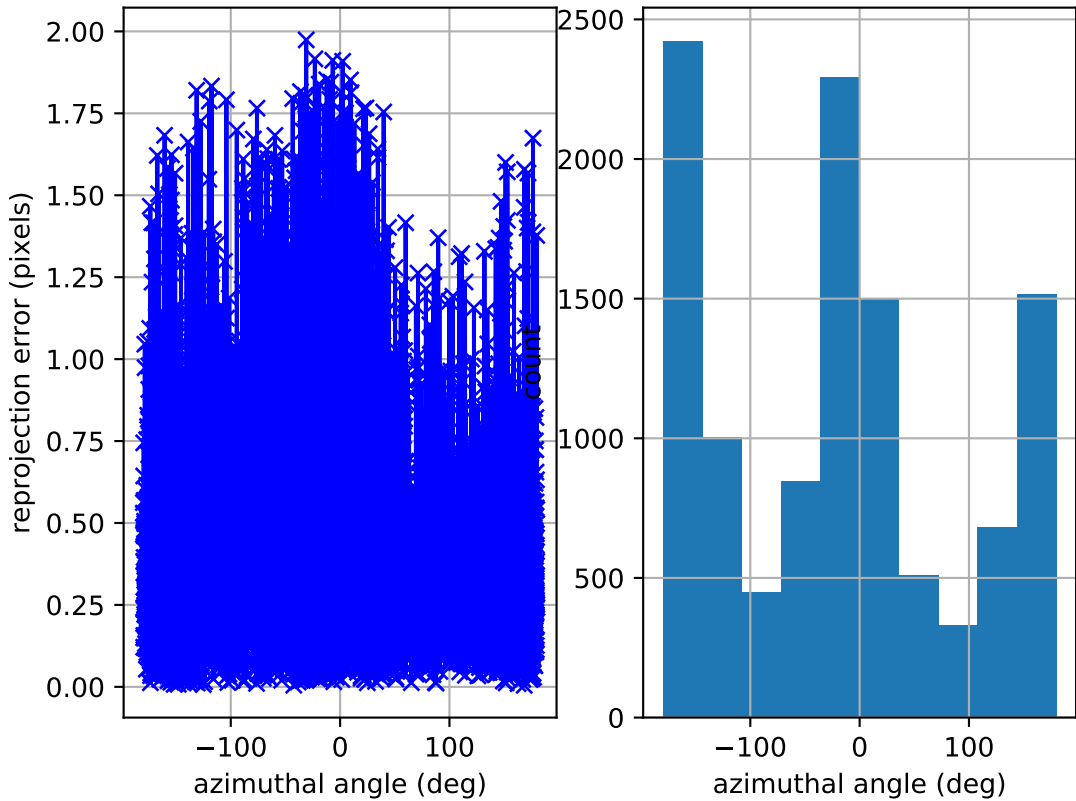
cam0: estimated poses



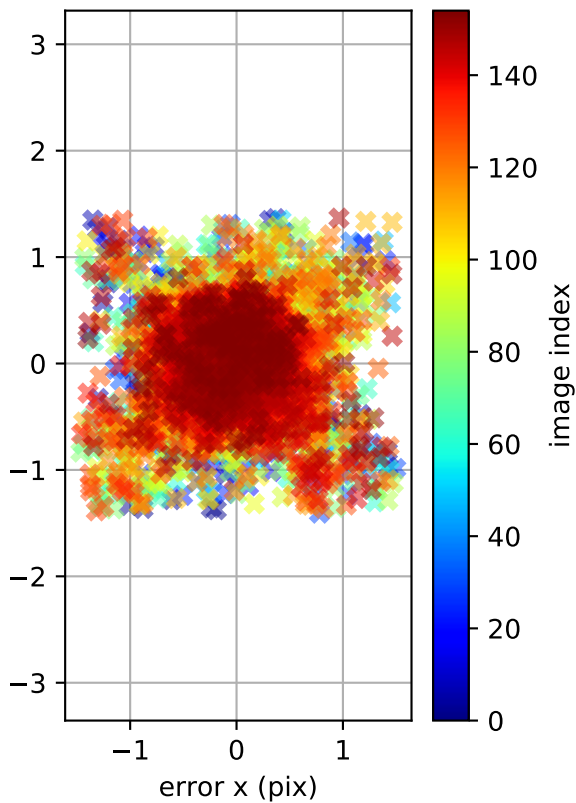
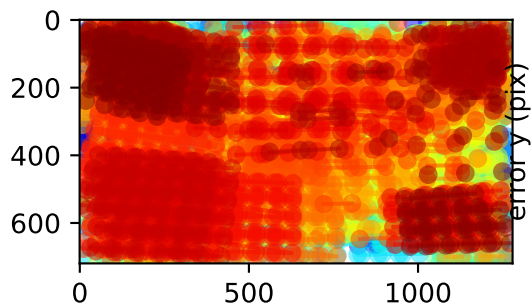
cam0: polar error



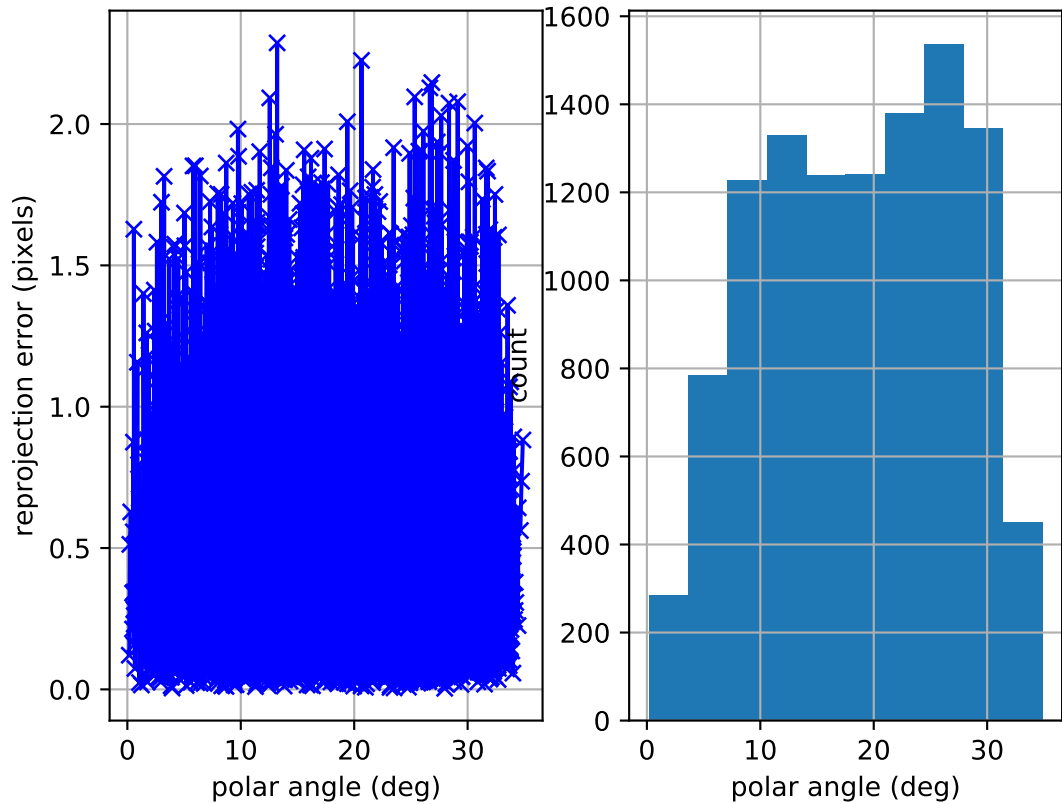
cam0: azimuthal error



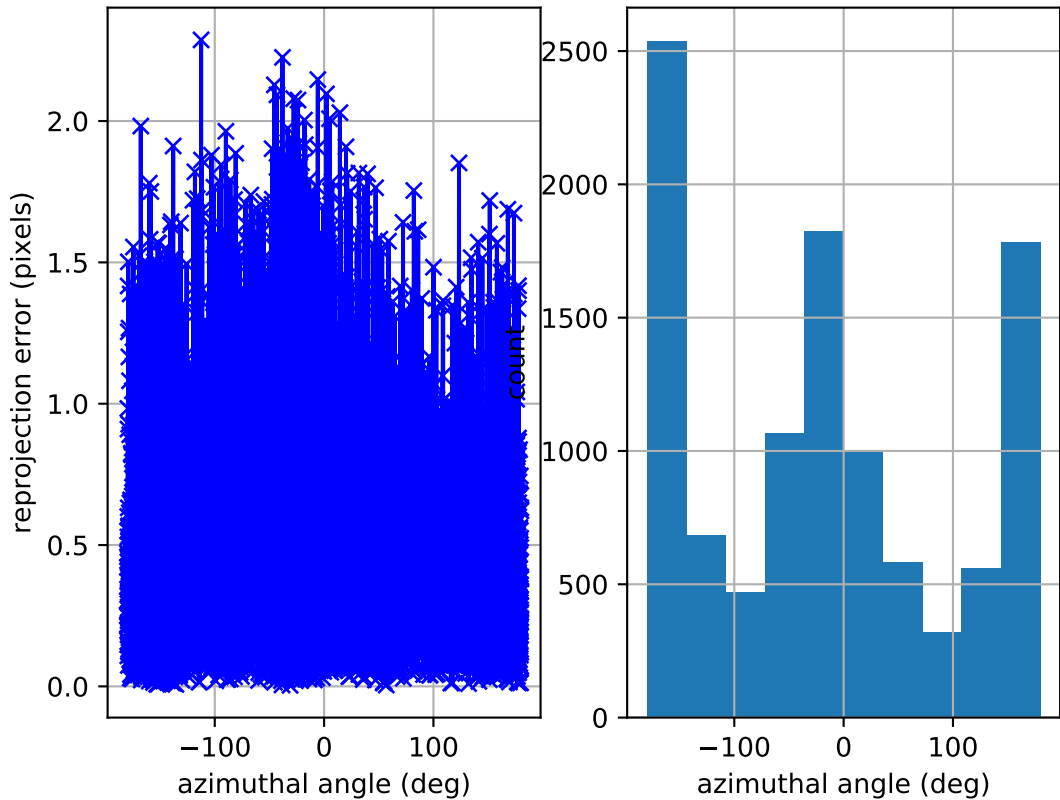
cam0: reprojection errors



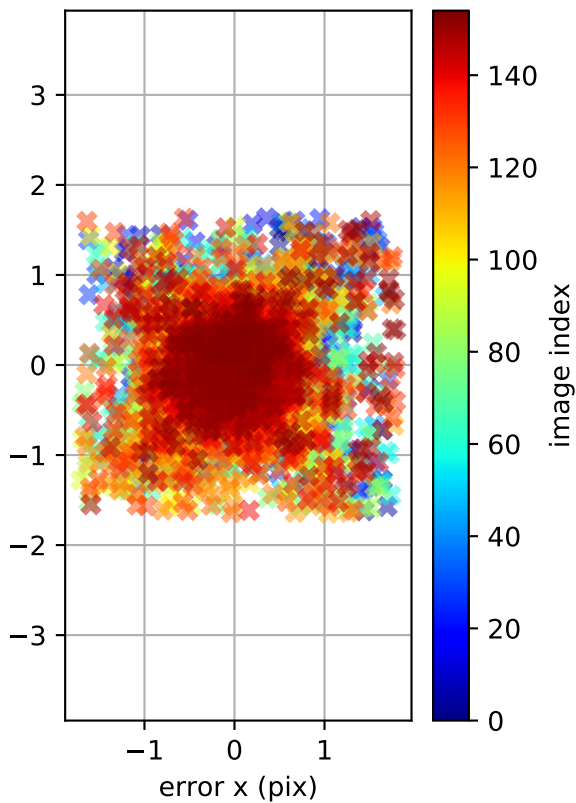
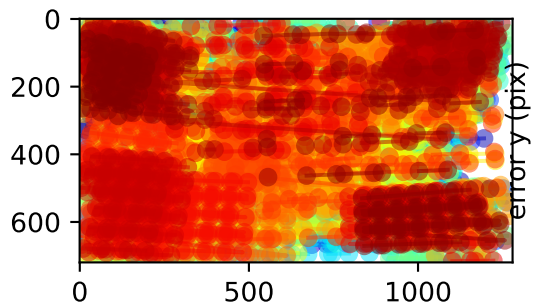
cam1: polar error



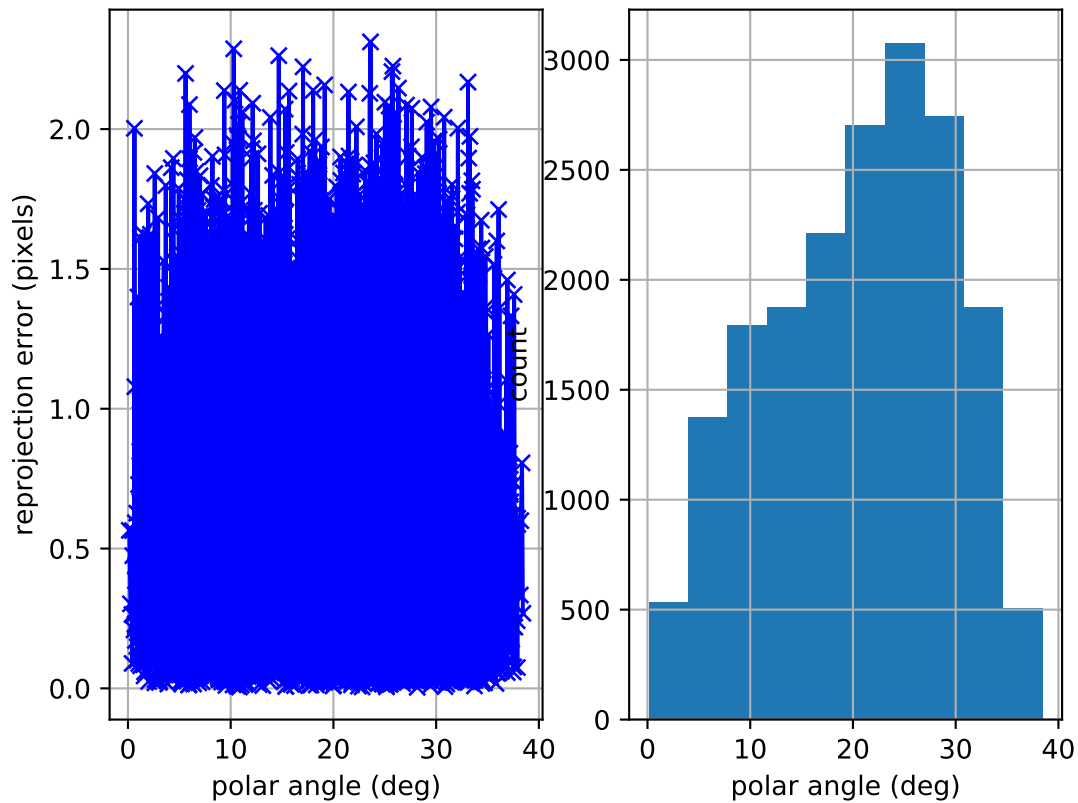
cam1: azimuthal error



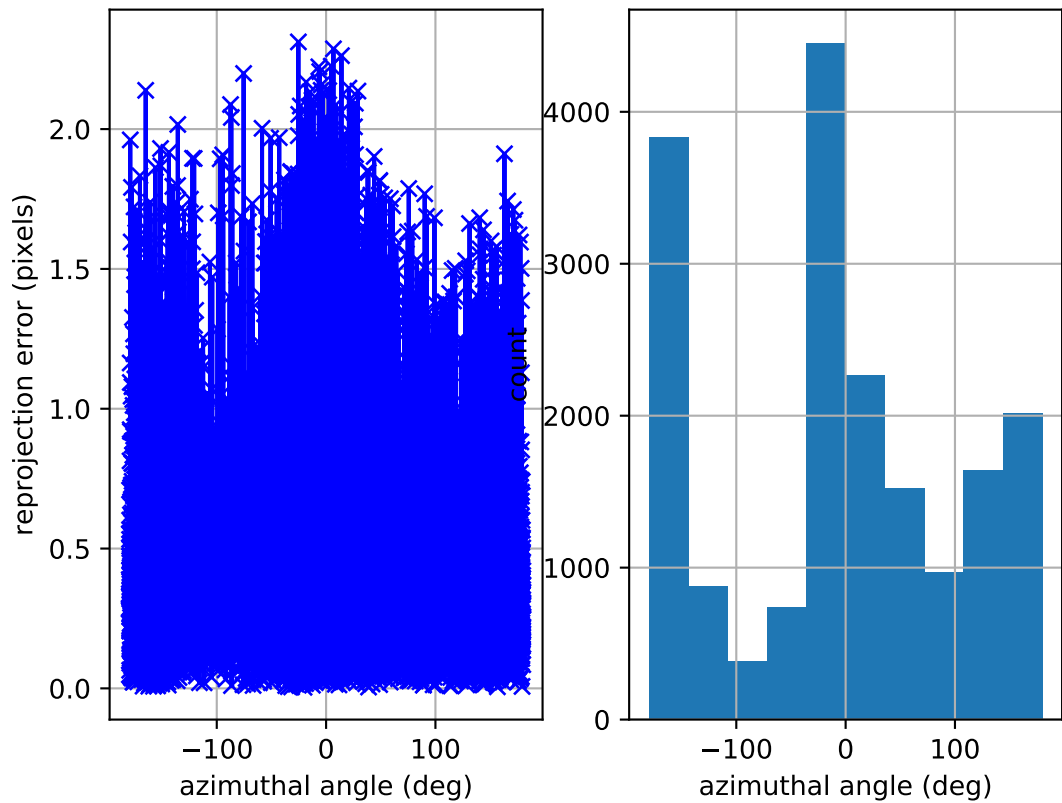
cam1: reprojection errors



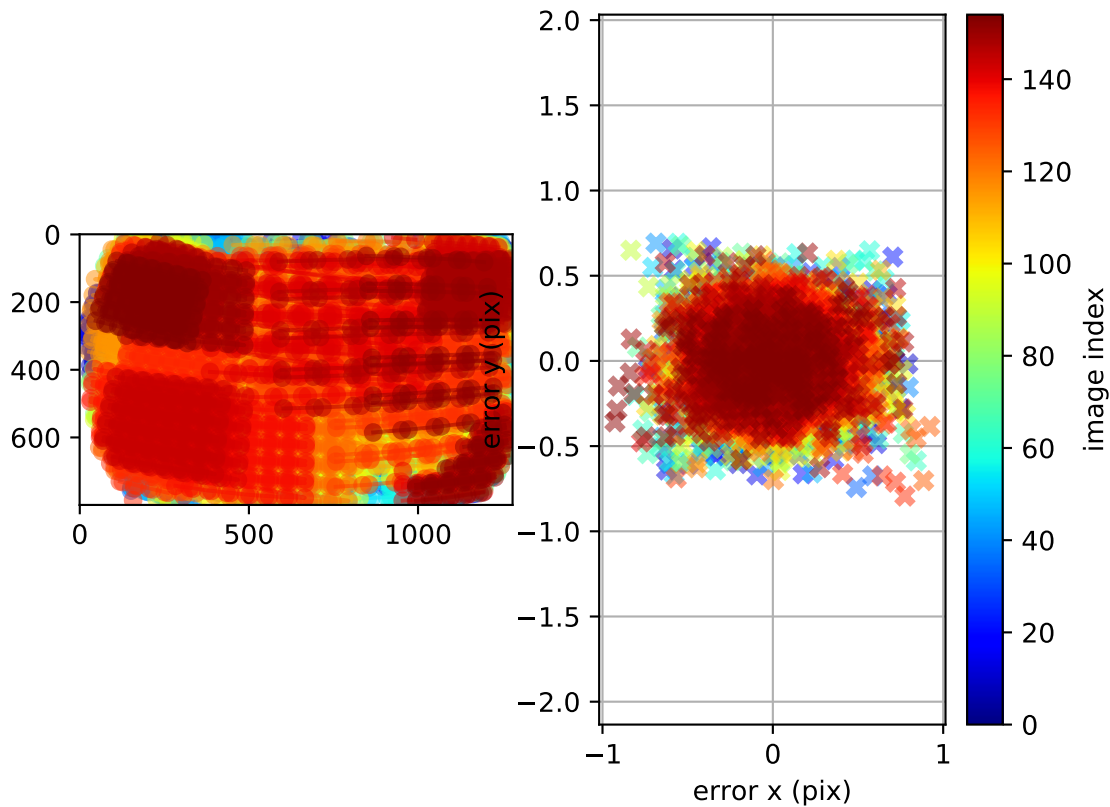
cam2: polar error



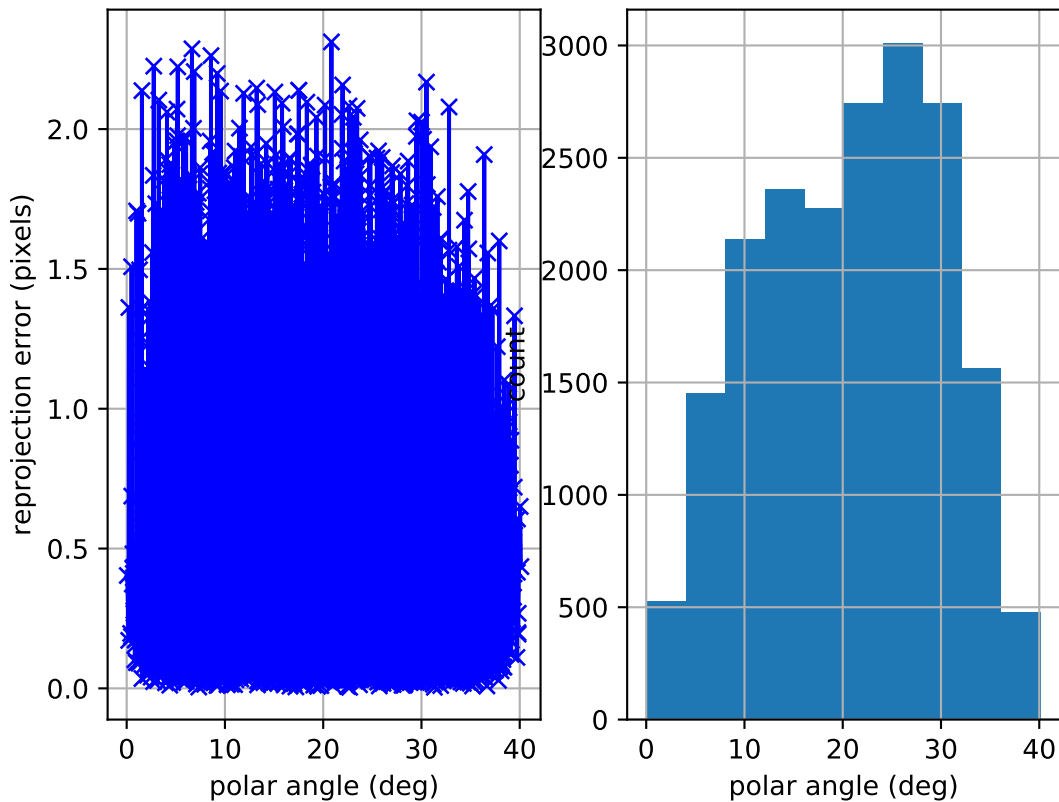
cam2: azimuthal error



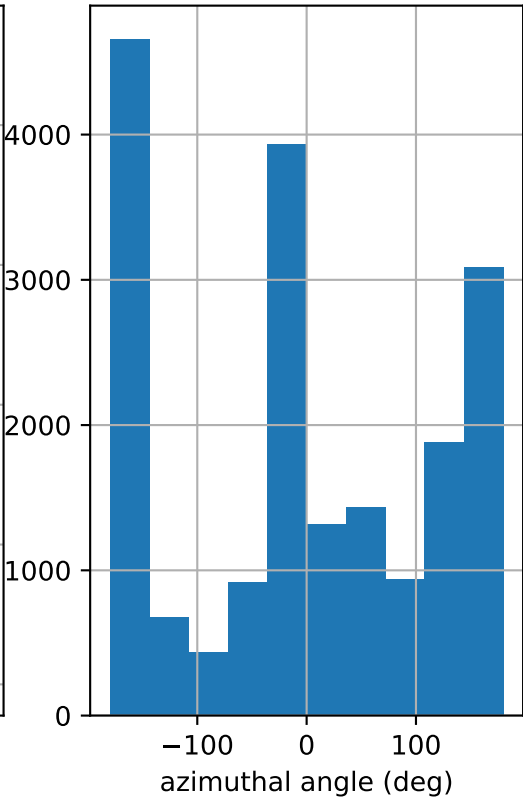
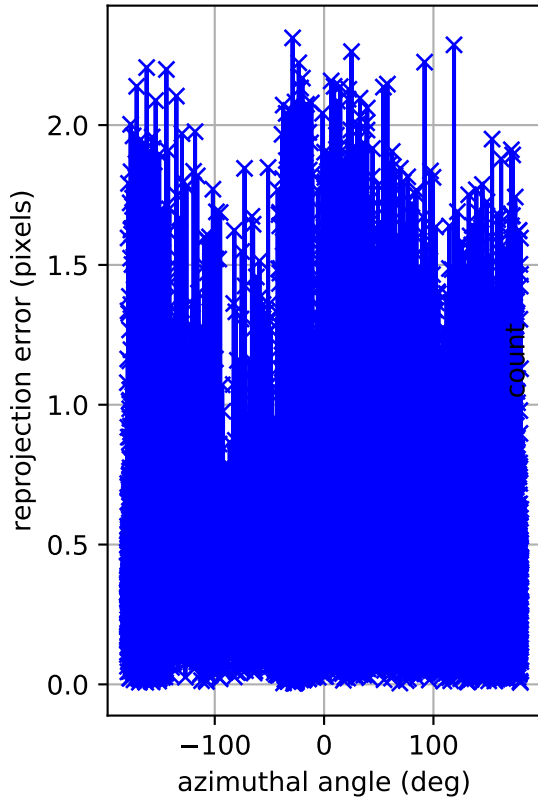
cam2: reprojection errors



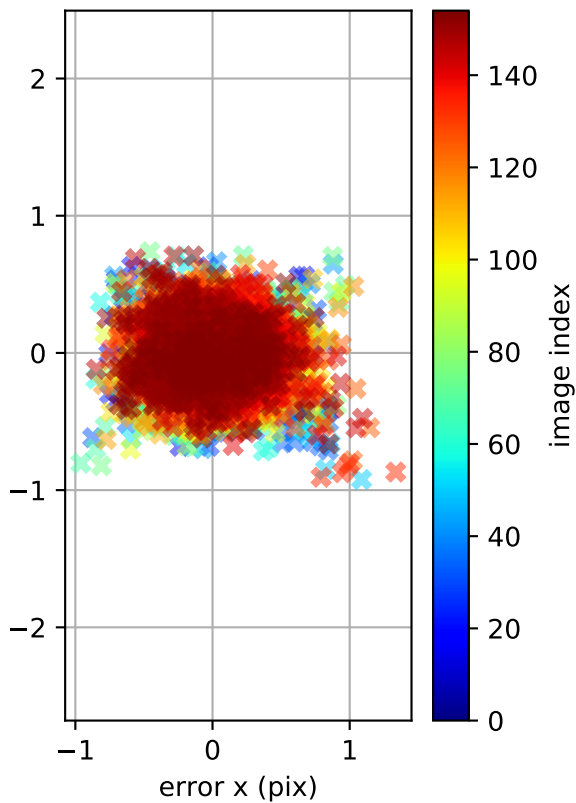
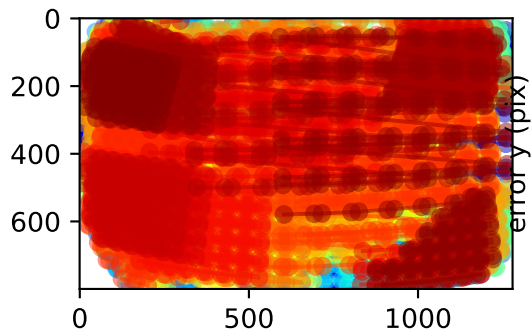
cam3: polar error



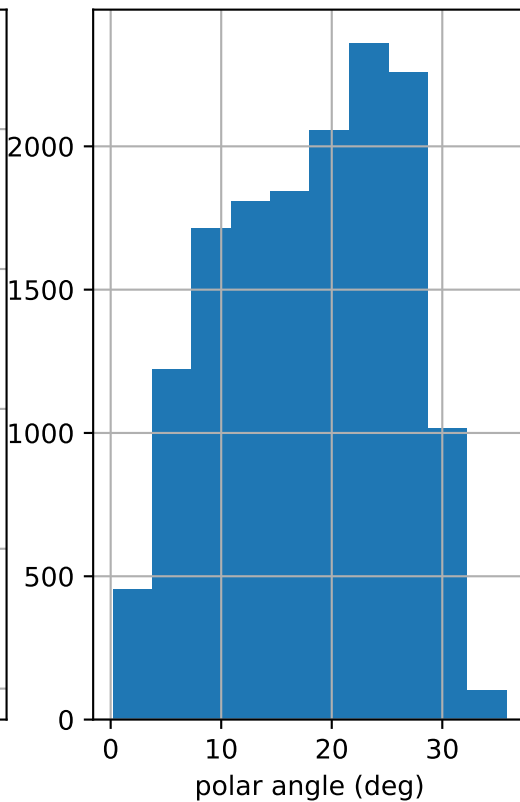
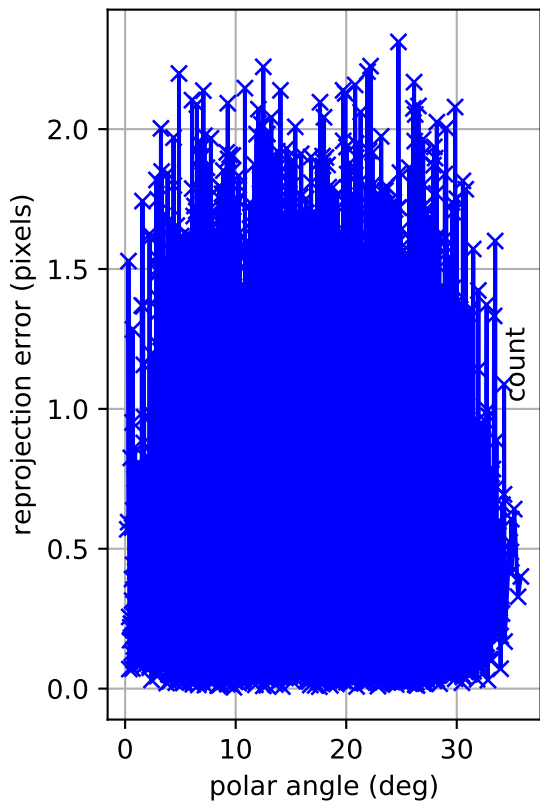
cam3: azimuthal error



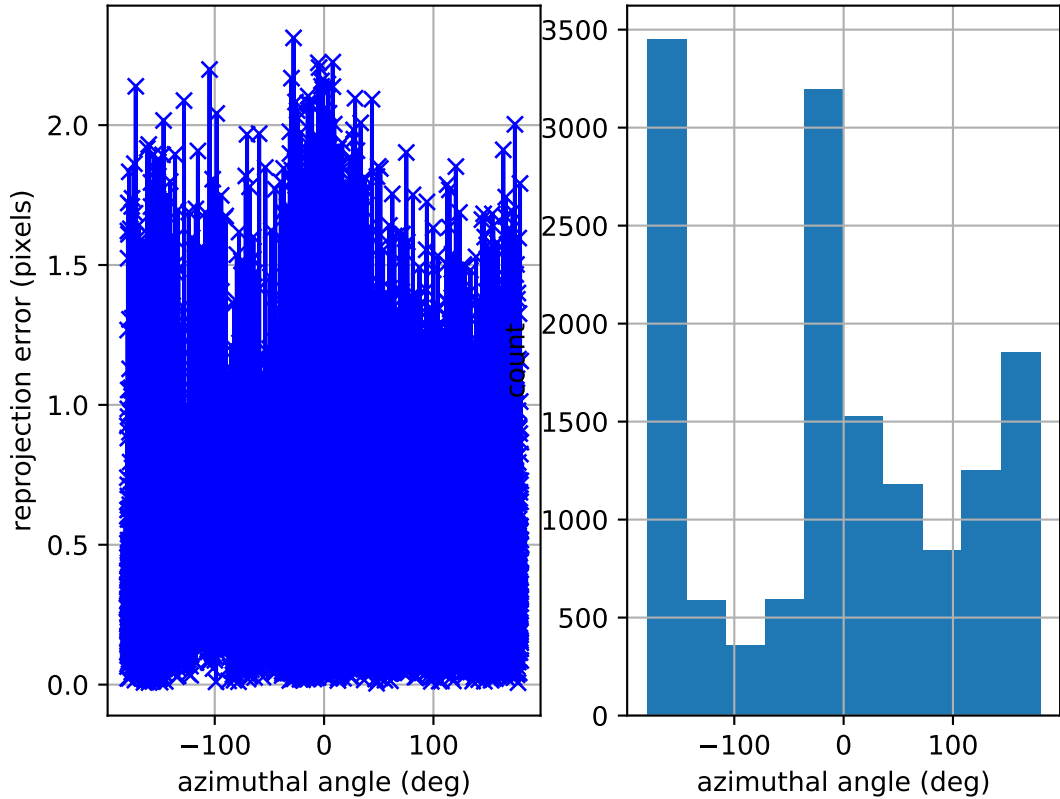
cam3: reprojection errors



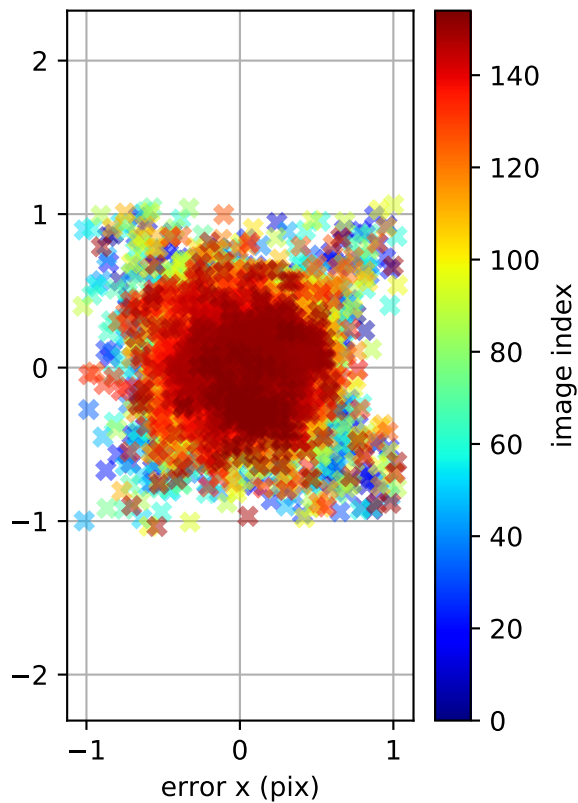
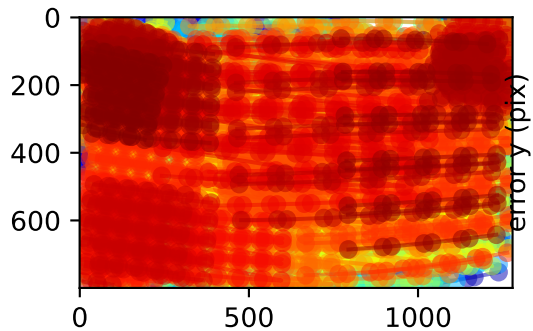
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

