

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04611144 0.0775785 0.00036698 -0.00133726] +- [0.00115733 0.00241339 0.00010151 0.00009341]
projection: [1031.18102119 1030.83691232 631.9231707 366.95610574] +- [0.13475344 0.12852216 0.00564363
0.09171785]

reprojection error: [0.000148, -0.000089] +- [0.465604, 0.418664]

cam1 (/prophesee/right/events):

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

distortion: [-0.05115049 0.07954807 0.00185753 -0.00085896] +- [0.00126285 0.00277016 0.00010599 0.00008522]
projection: [1030.15875285 1030.2579565 631.3861432 369.60814439] +- [0.15015511 0.14346932 0.0026636
0.09105898]

reprojection error: [0.000225, -0.000091] +- [0.596908, 0.574551]

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

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

distortion: [-0.39653829 0.16370161 -0.00040434 0.00123175] +- [0.000638 0.00114764 0.00006921 0.00006386]
projection: [1057.36745924 1057.69080723 669.43317543 337.45047254] +- [0.10681539 0.10305602 0.03243373
0.23795097]

reprojection error: [0.000328, -0.000095] +- [0.196253, 0.175706]

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

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

distortion: [-0.39312525 0.15454431 -0.00056034 0.00184348] +- [0.00053401 0.00085141 0.00006926 0.00005386]
projection: [1051.82876471 1052.7795664 666.25041435 330.21989705] +- [0.10770198 0.1030929 0.00762339
0.2277641]

reprojection error: [0.000377, -0.000096] +- [0.217531, 0.181611]

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

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

distortion: [-0.4168483 0.19200443 -0.00035457 0.00060025] +- [0.00093237 0.00237612 0.00007298 0.00006252]
projection: [1263.17619093 1263.27171197 647.81241892 370.14894155] +- [0.120487 0.11352512 0.02626188
0.11861291]

reprojection error: [0.000168, -0.000175] +- [0.210847, 0.188277]

baseline T_1_0:

q: [-0.00161031 0.00132788 -0.00028298 0.99999778] +- [0.00005453 0.00005011 0.00004667]

t: [-0.12021897 0.0010254 0.00007386] +- [0.00003788 0.0000372 0.00012776]

baseline T_2_1:

q: [-0.00011806 -0.00300518 -0.00506513 0.99998265] +- [0.00028938 0.00005496 0.00004415]

t: [0.12027418 0.06903322 0.00386372] +- [0.00003378 0.00003299 0.000118]

baseline T_3_2:

q: [0.00021389 -0.00278898 0.00020076 0.99999607] +- [0.00032145 0.00005166 0.00003489]

t: [-0.12004999 -0.00010306 0.00148382] +- [0.00002577 0.00002338 0.00009476]

baseline T_4_3:

q: [0.00156554 0.00594157 0.00052576 0.99998099] +- [0.0002845 0.00003499 0.00003438]

t: [0.08890544 0.00615919 0.00301835] +- [0.0000242 0.00002196 0.00009003]

Target configuration

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Type: aprilgrid

Tags:

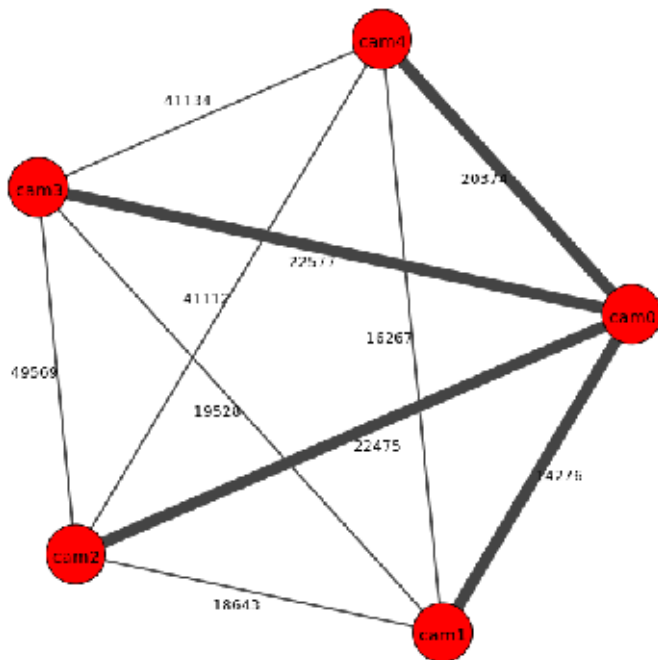
Rows: 5

Cols: 7

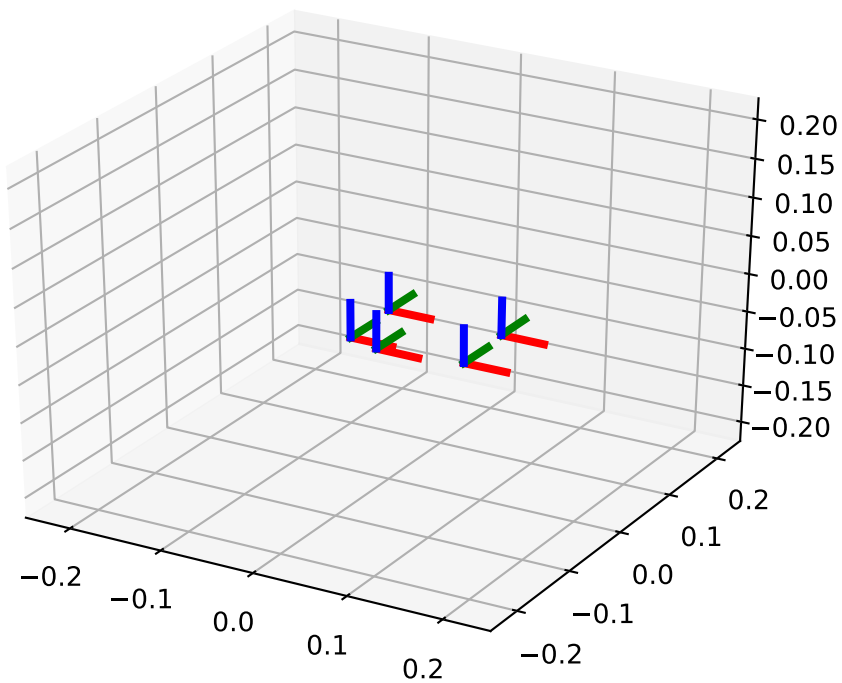
Size: 0.04 [m]

Spacing 0.01 [m]

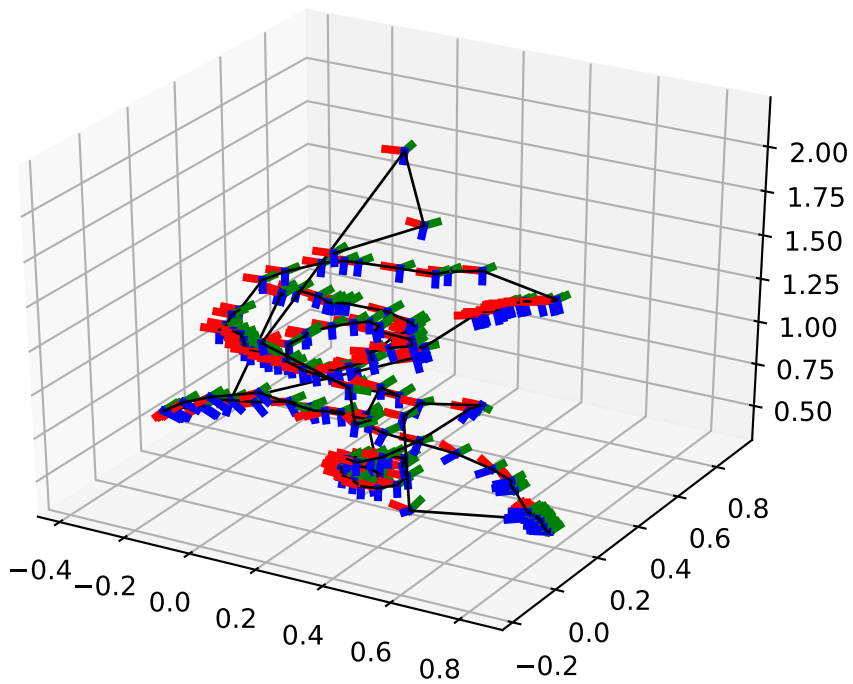
Inter-camera observations graph (edge weight=#mutual obs.)



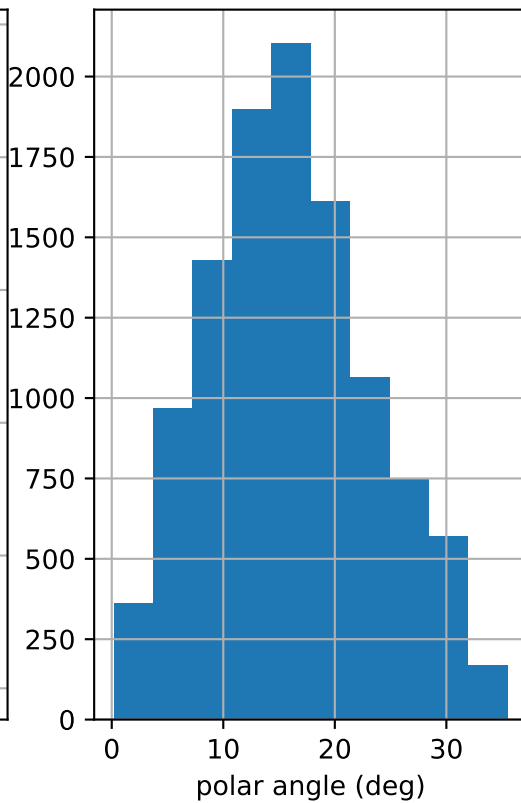
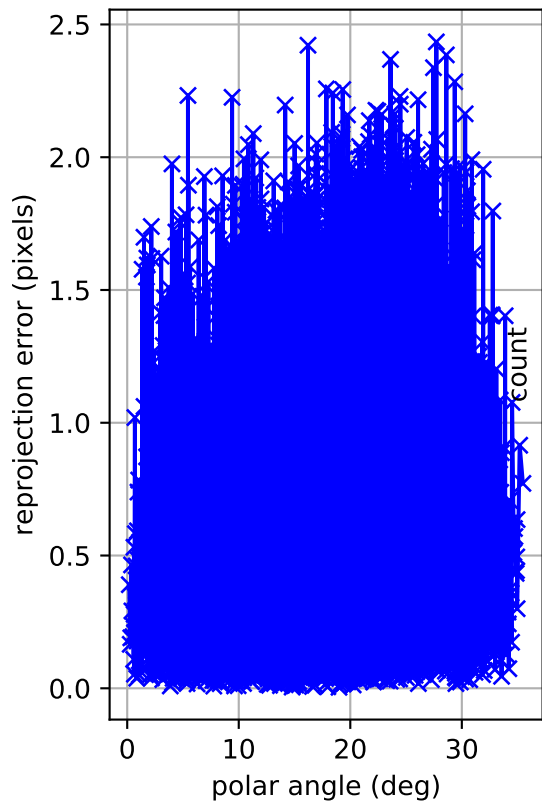
camera system



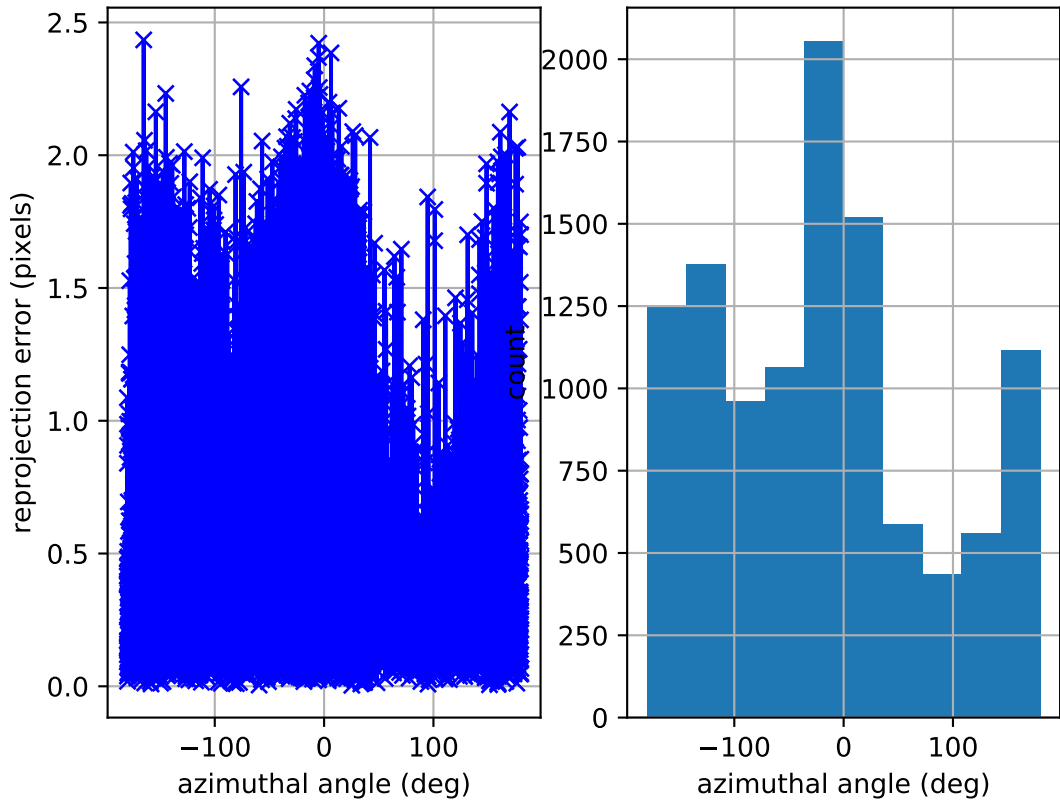
cam0: estimated poses



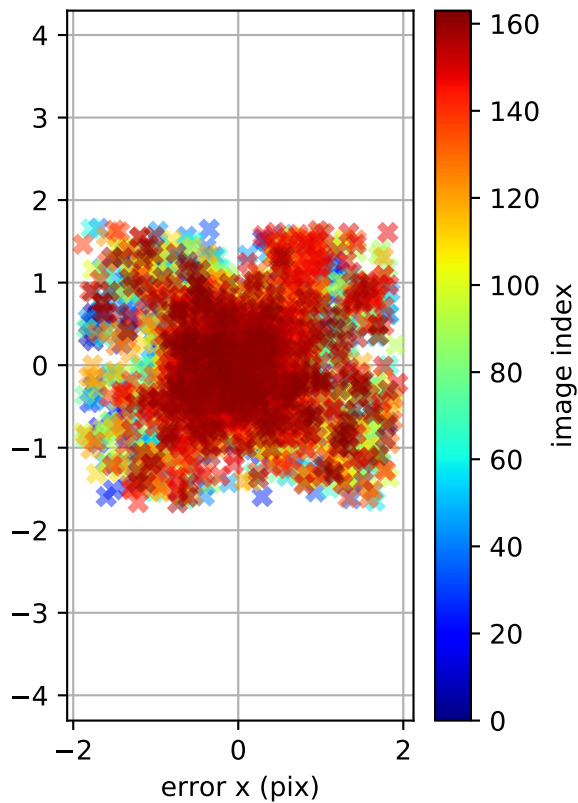
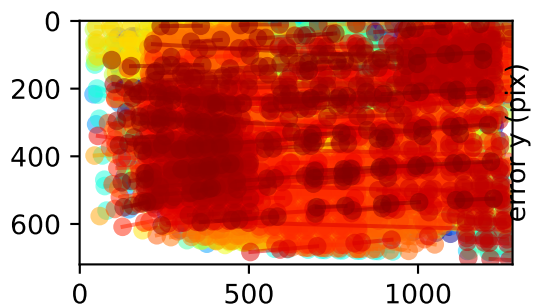
cam0: polar error



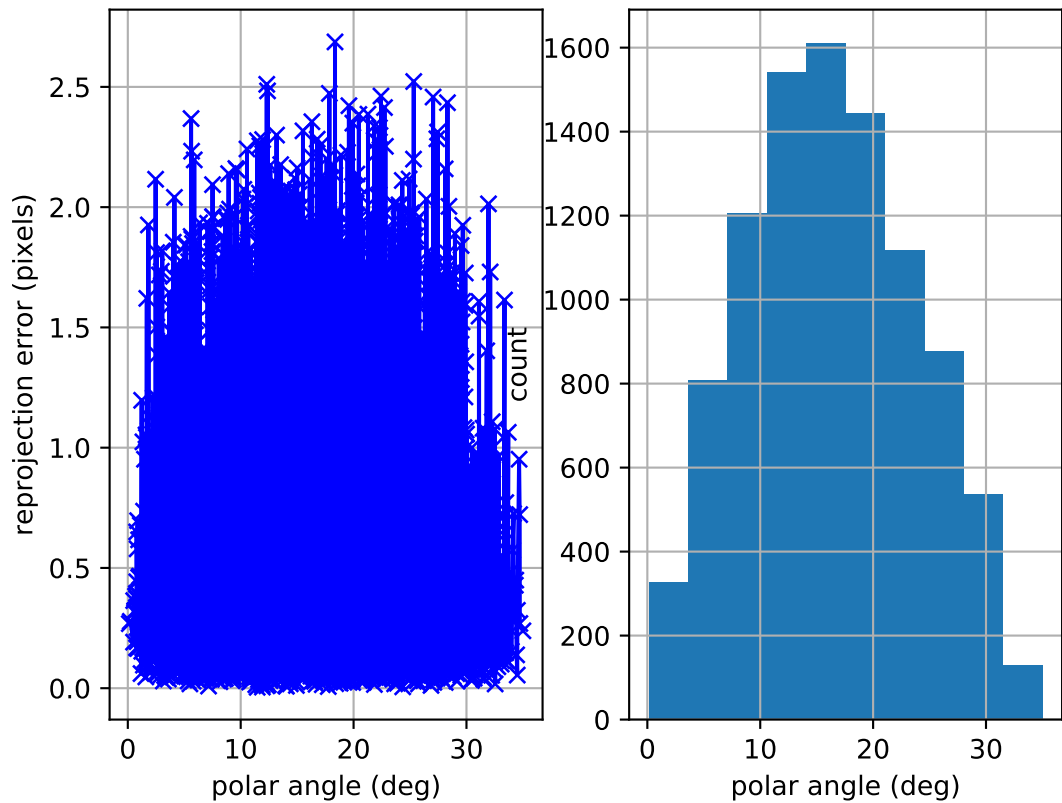
cam0: azimuthal error



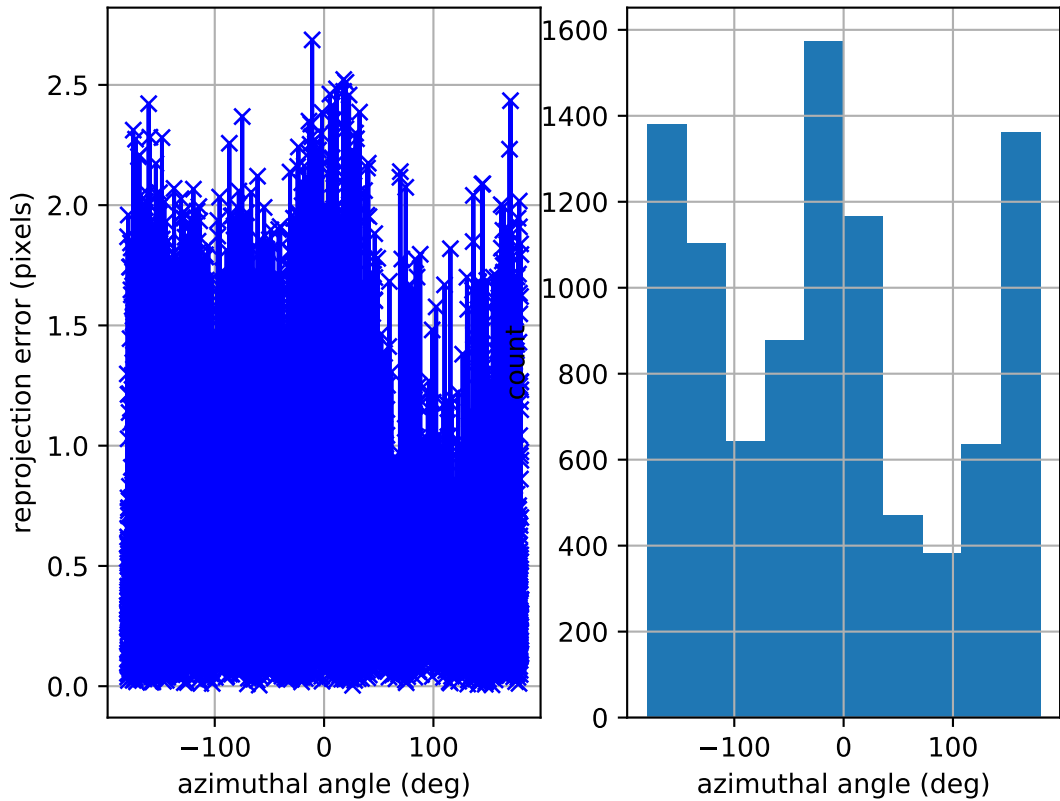
cam0: reprojection errors



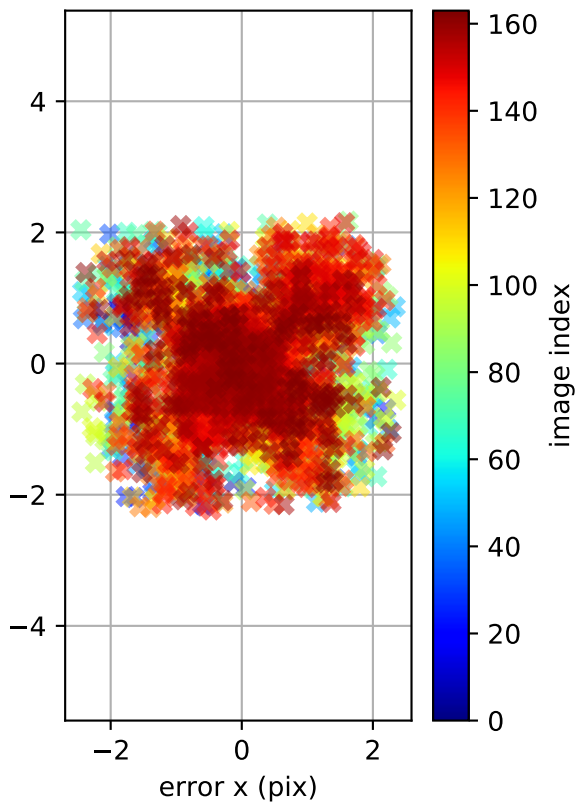
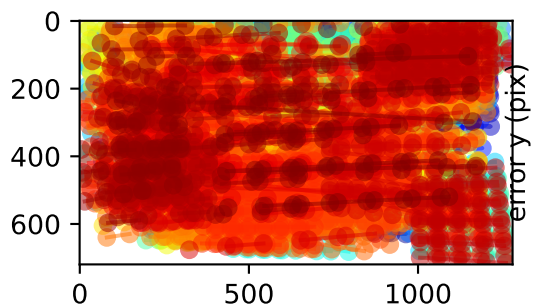
cam1: polar error



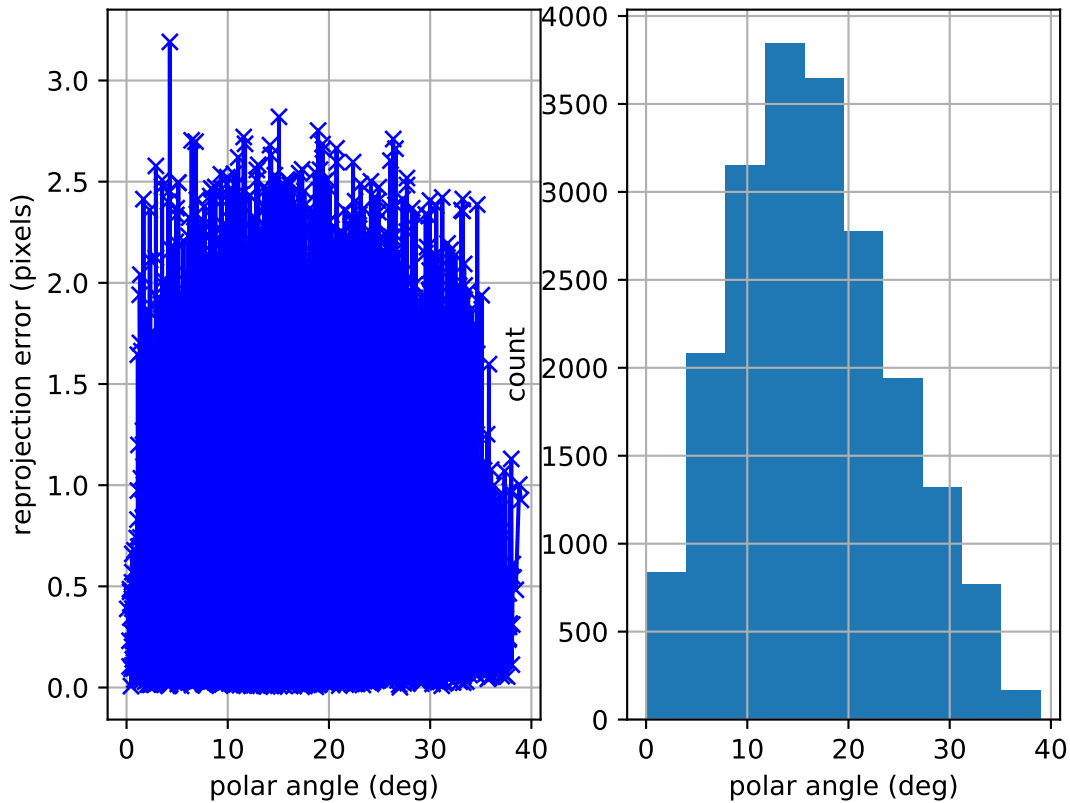
cam1: azimuthal error



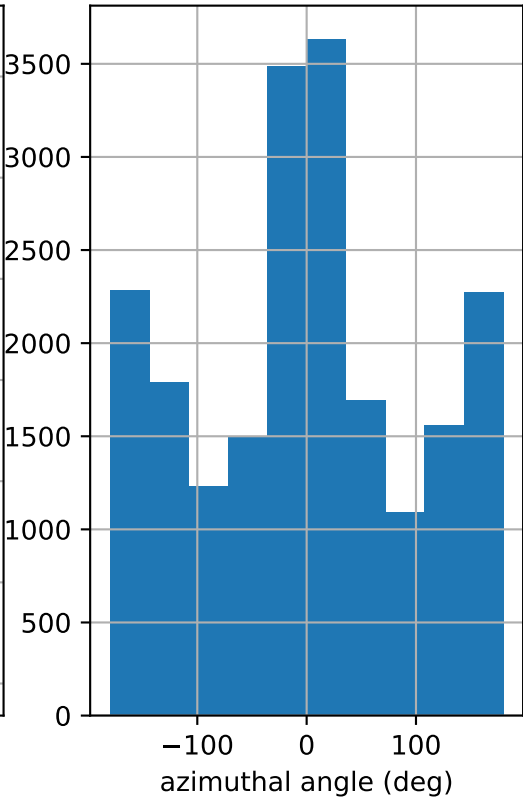
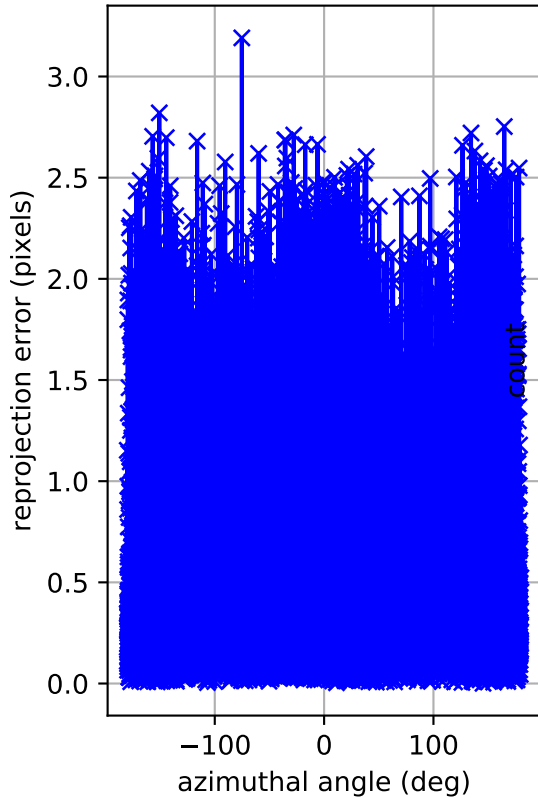
cam1: reprojection errors



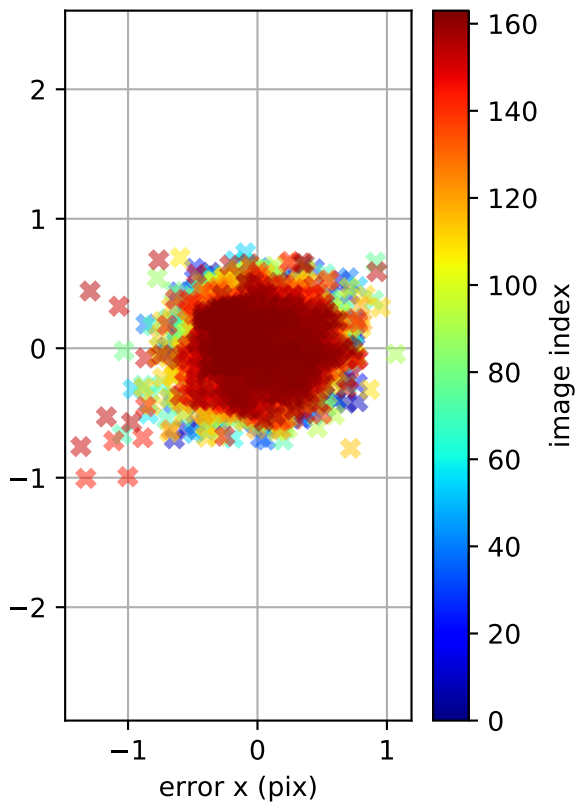
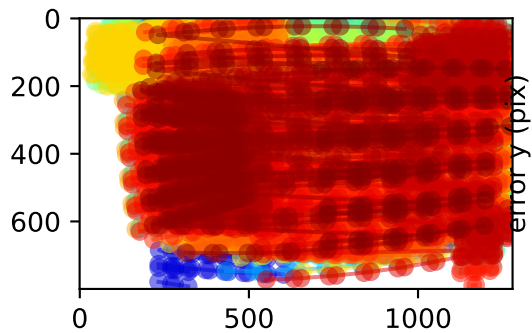
cam2: polar error



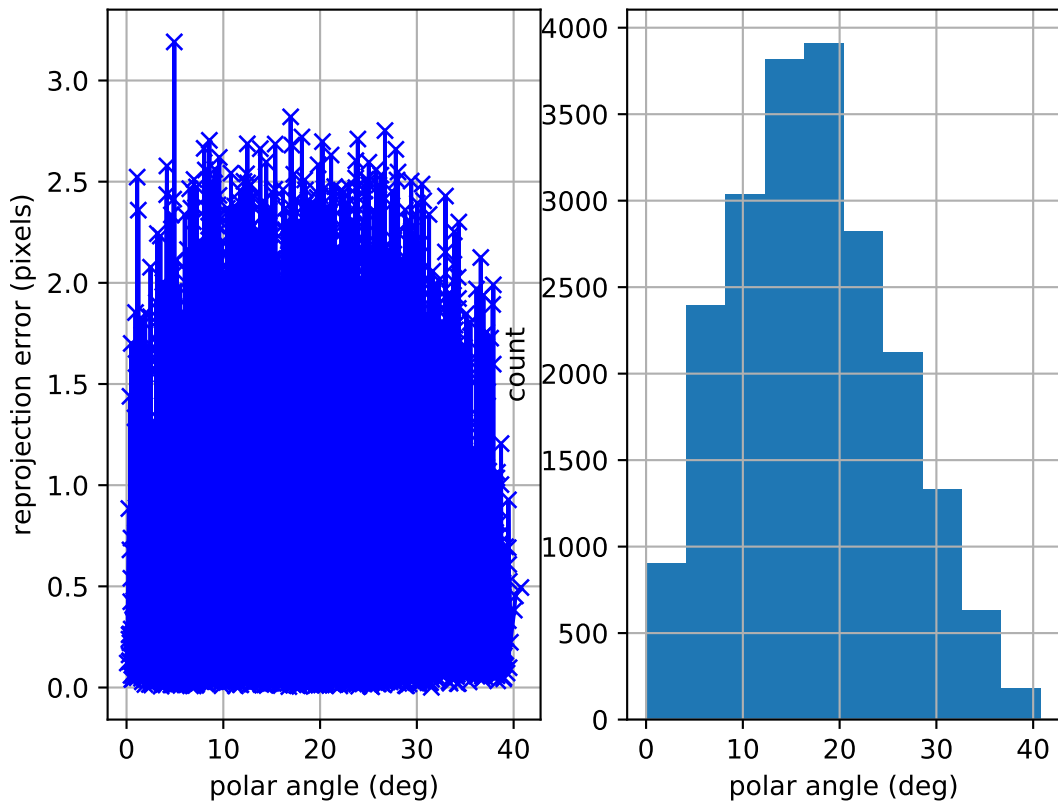
cam2: azimuthal error



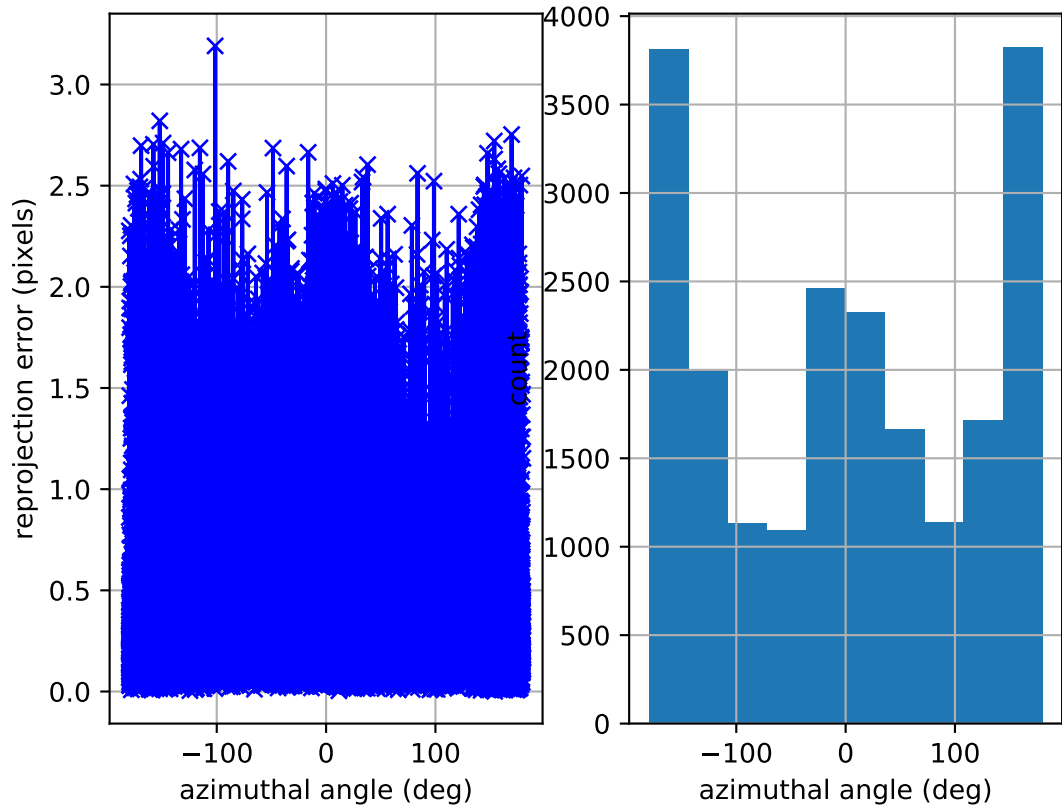
cam2: reprojection errors



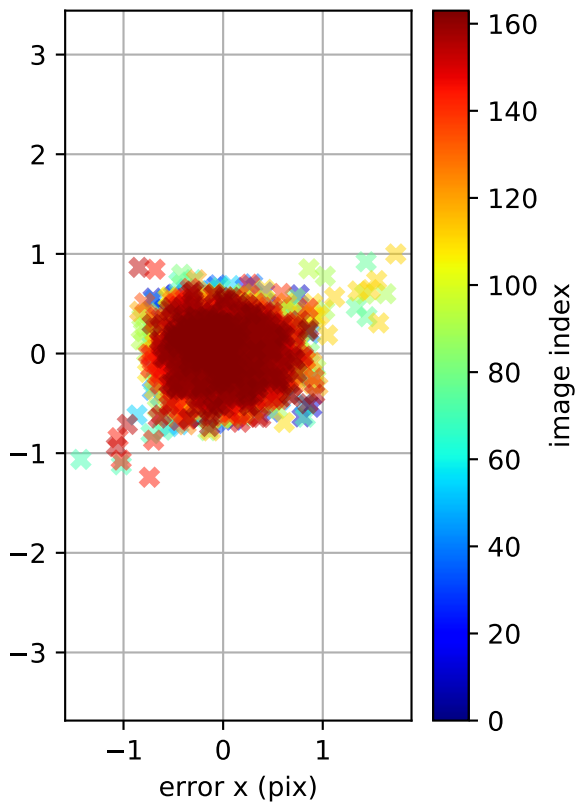
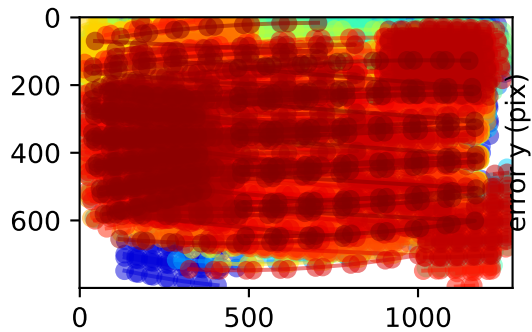
cam3: polar error



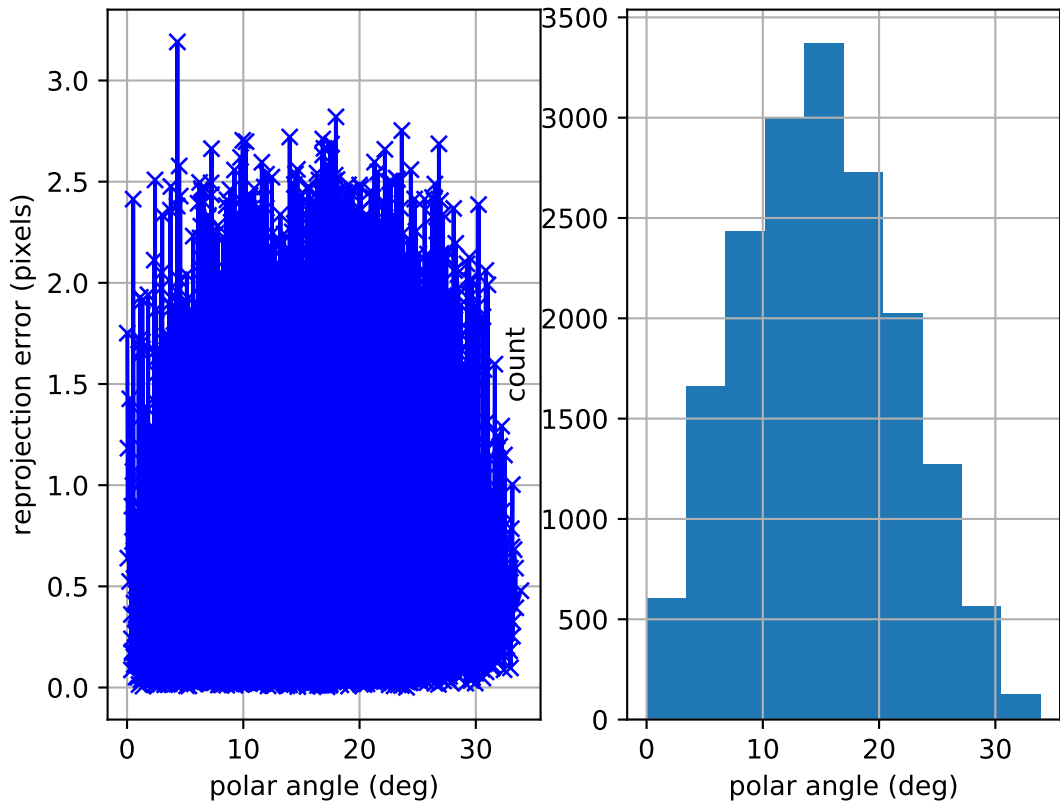
cam3: azimuthal error



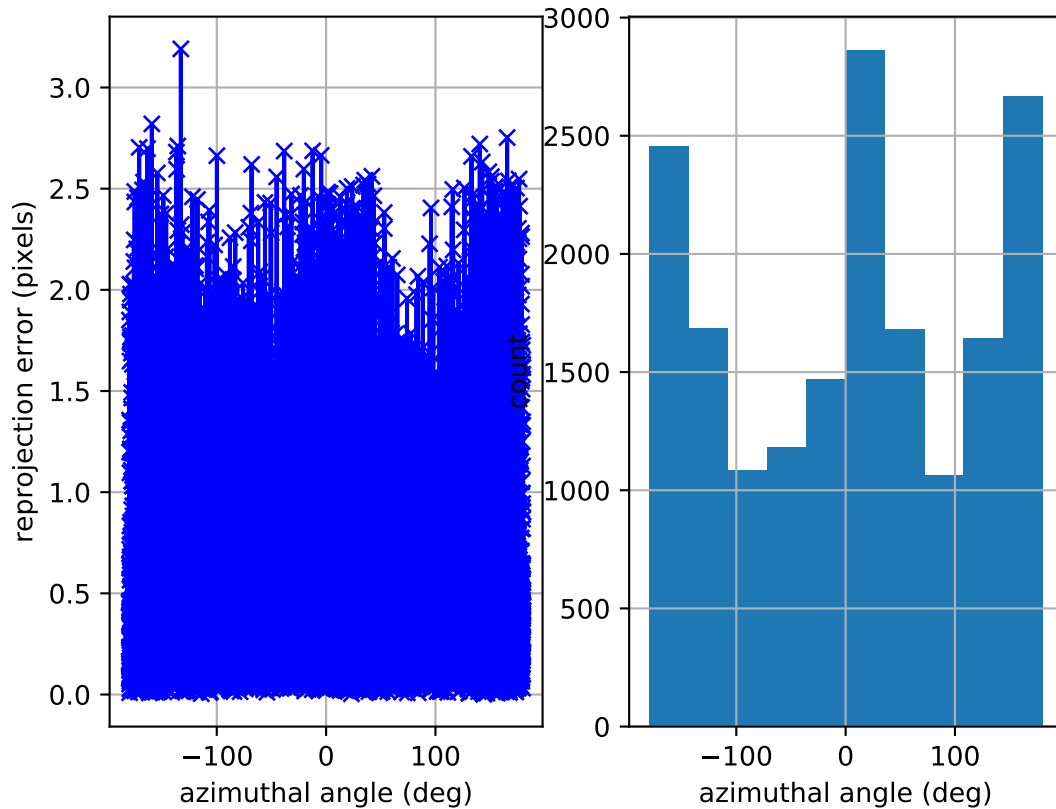
cam3: reprojection errors



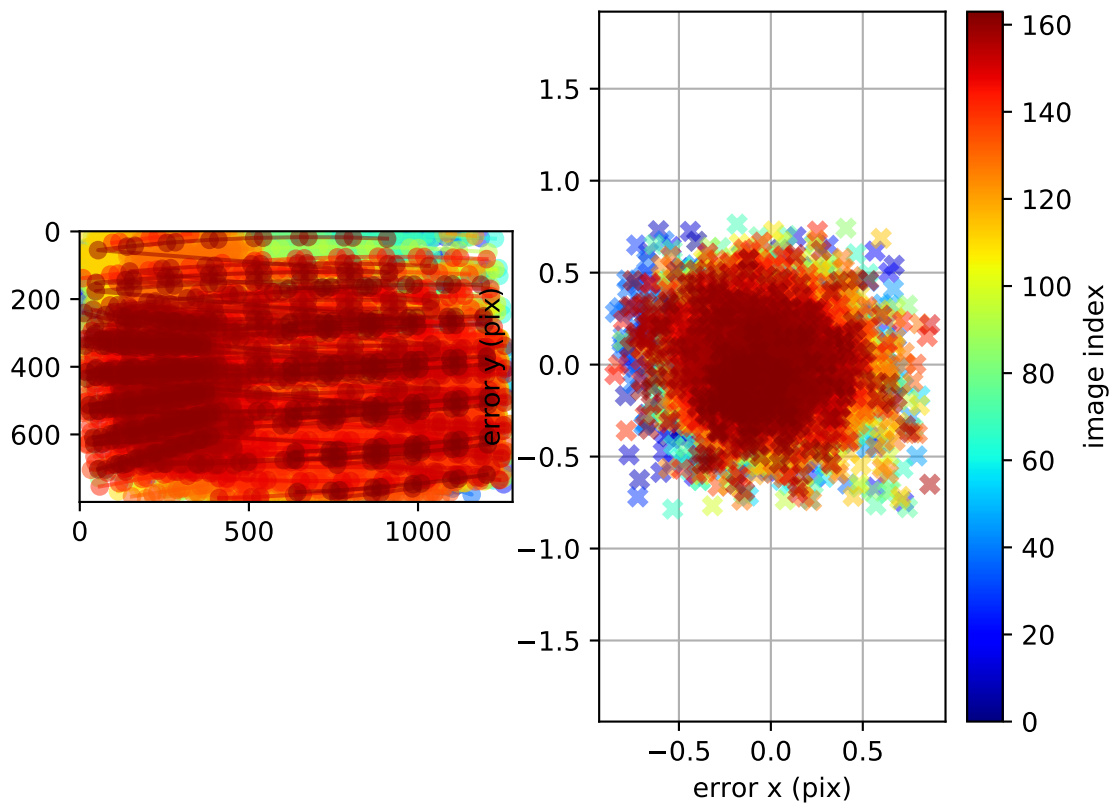
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

