

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04364643 0.07180625 0.00092213 -0.00042403] +- [0.00100824 0.00211497 0.00009725 0.00007647]
projection: [1031.96208381 1031.83221391 637.97533213 367.507214] +- [0.13843153 0.13789303 0.03517469
0.20928276]

reprojection error: [-0.000068, -0.000071] +- [0.517919, 0.470345]

cam1 (/prophesee/right/events):

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

distortion: [-0.04709002 0.06717322 0.00200528 0.00051354] +- [0.00108227 0.00221794 0.0000964 0.00007765]
projection: [1031.19326792 1030.99426672 639.38951597 368.77569497] +- [0.14937266 0.15021601 0.01086162
0.20352579]

reprojection error: [-0.000077, -0.000111] +- [0.655567, 0.596429]

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

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

distortion: [-0.39440555 0.15840272 -0.00016896 0.00010441] +- [0.00054227 0.0009562 0.00005898 0.00004993]
projection: [1056.89258505 1057.26495784 678.63918609 337.36566296] +- [0.1103255 0.11036885 0.01727472
0.1832257]

reprojection error: [-0.000012, -0.000157] +- [0.202692, 0.176037]

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

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

distortion: [-0.39183209 0.15139664 -0.00024058 0.00053019] +- [0.00048702 0.00076653 0.0000595 0.00005052]
projection: [1051.42556174 1051.85920994 679.12359245 329.25425525] +- [0.10683181 0.11087046 0.02620999
0.17527202]

reprojection error: [0.000031, -0.000115] +- [0.223535, 0.189022]

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

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

distortion: [-0.41267929 0.17743308 -0.00024559 -0.00056937] +- [0.00099427 0.00262655 0.00007113 0.0000544]
projection: [1262.82852152 1262.48244309 656.486549 370.36968122] +- [0.13398947 0.13847455 0.00344356
0.03555188]

reprojection error: [-0.000008, -0.000170] +- [0.494746, 0.540805]

baseline T_1_0:

q: [-0.00091683 0.00212089 -0.00040065 0.99999725] +- [0.00035178 0.00006161 0.00004004]

t: [-0.12025646 0.00092706 -0.00053117] +- [0.00003248 0.00003045 0.00011153]

baseline T_2_1:

q: [-0.00027891 -0.0022866 -0.00513737 0.99998415] +- [0.00032007 0.00004428 0.00003614]

t: [0.120181 0.06914301 0.00383756] +- [0.00002886 0.00002636 0.00009863]

baseline T_3_2:

q: [0.00061205 -0.00106299 0.00020494 0.99999923] +- [0.00026321 0.00004482 0.0000297]

t: [-0.12009721 -0.00011986 0.00009049] +- [0.0000232 0.00002018 0.00008033]

baseline T_4_3:

q: [0.00102616 0.003229 0.00042106 0.99999417] +- [0.00018654 0.00004555 0.00003361]

t: [0.08890122 0.00619542 0.00367307] +- [0.00002368 0.00002116 0.0000812]

Target configuration

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Type: aprilgrid

Tags:

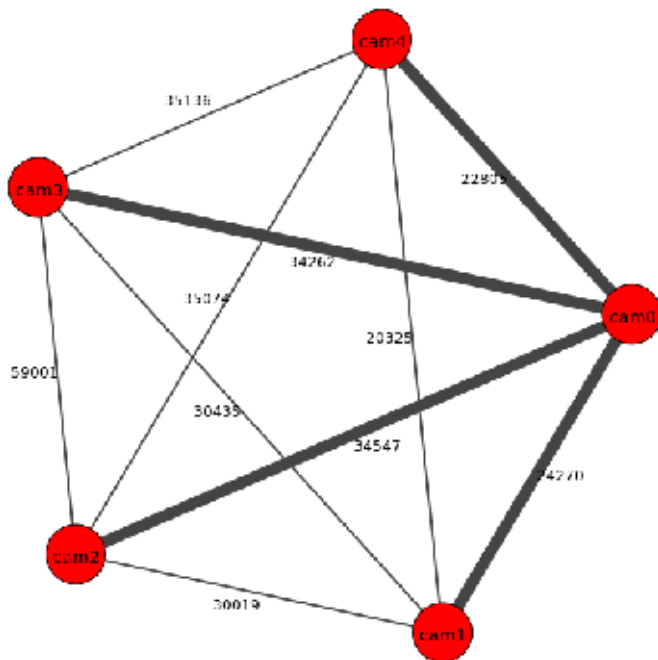
Rows: 5

Cols: 7

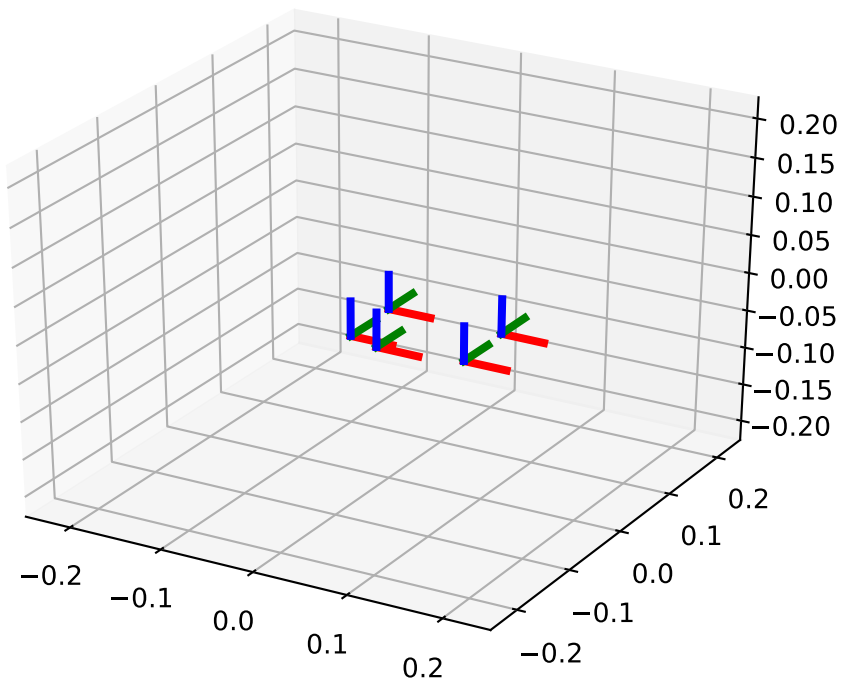
Size: 0.04 [m]

Spacing 0.01 [m]

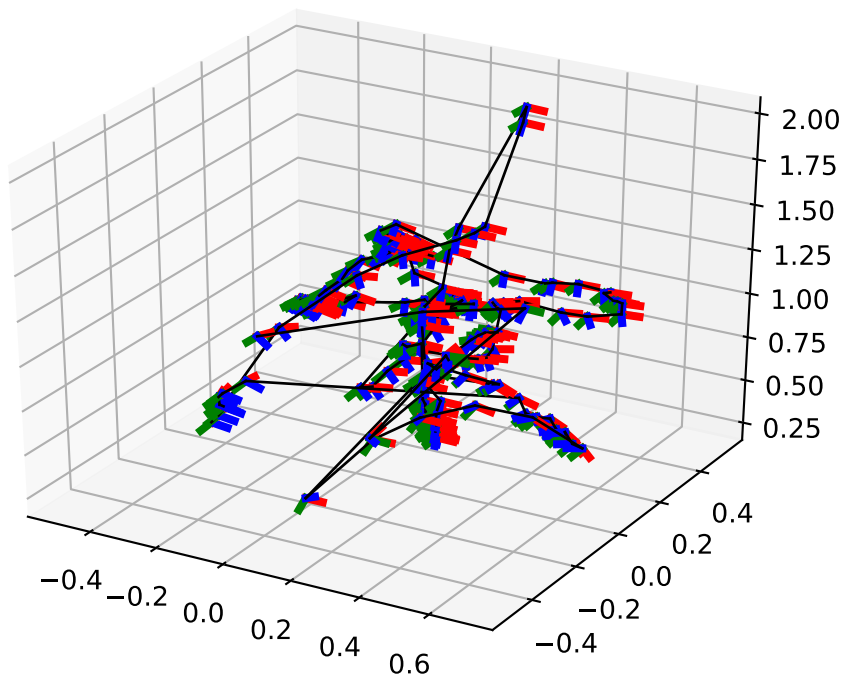
Inter-camera observations graph (edge weight=#mutual obs.)



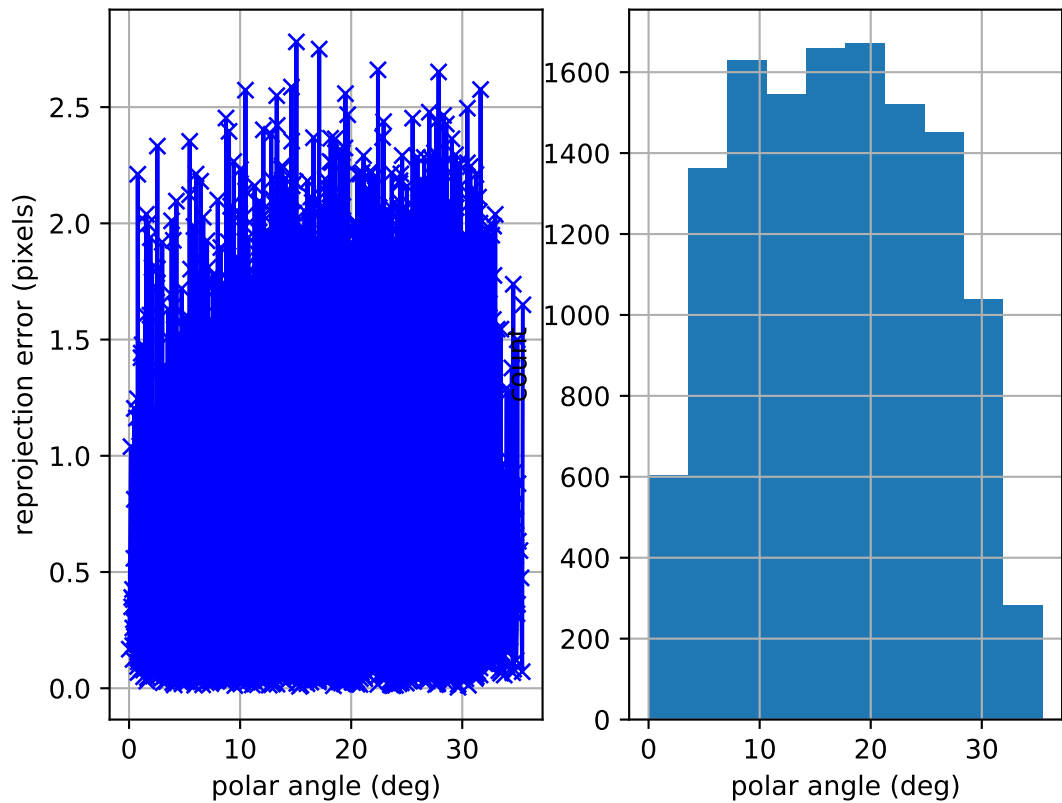
camera system



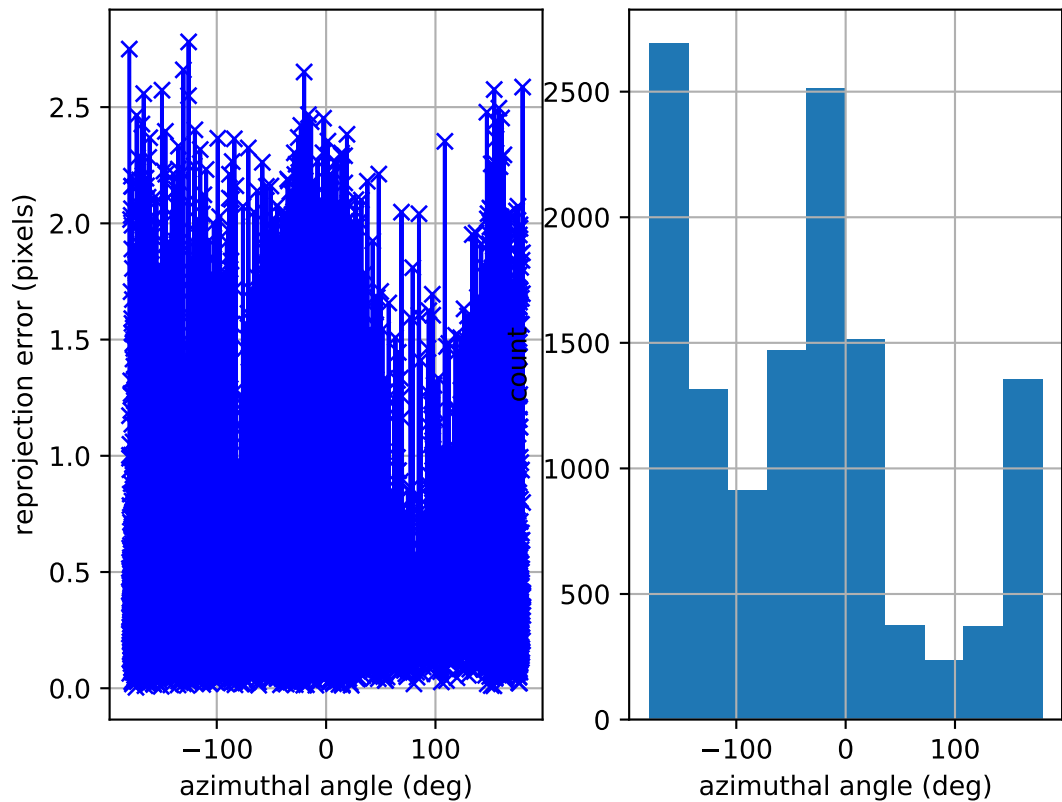
cam0: estimated poses



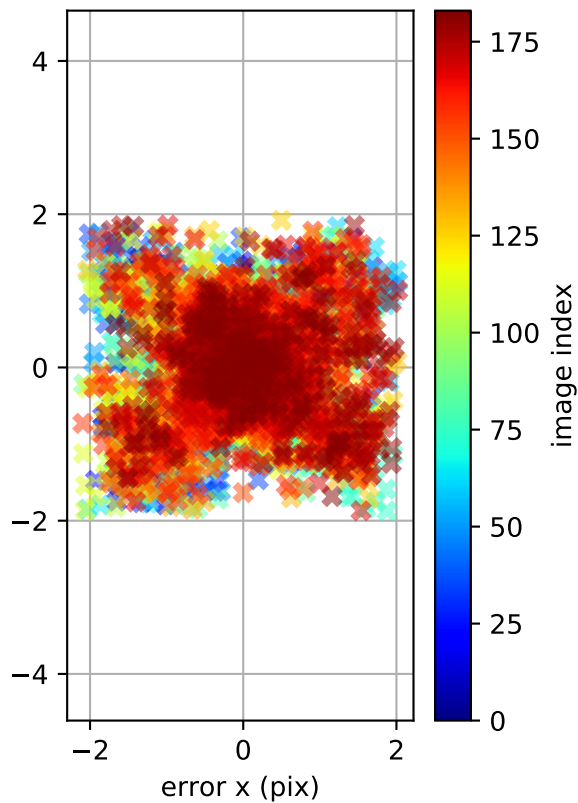
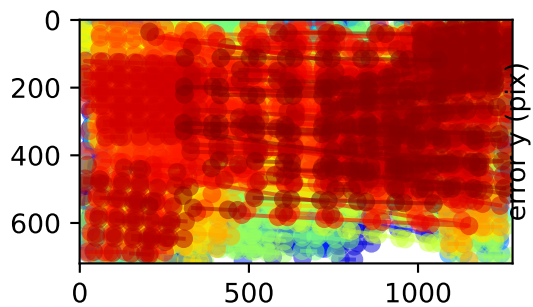
cam0: polar error



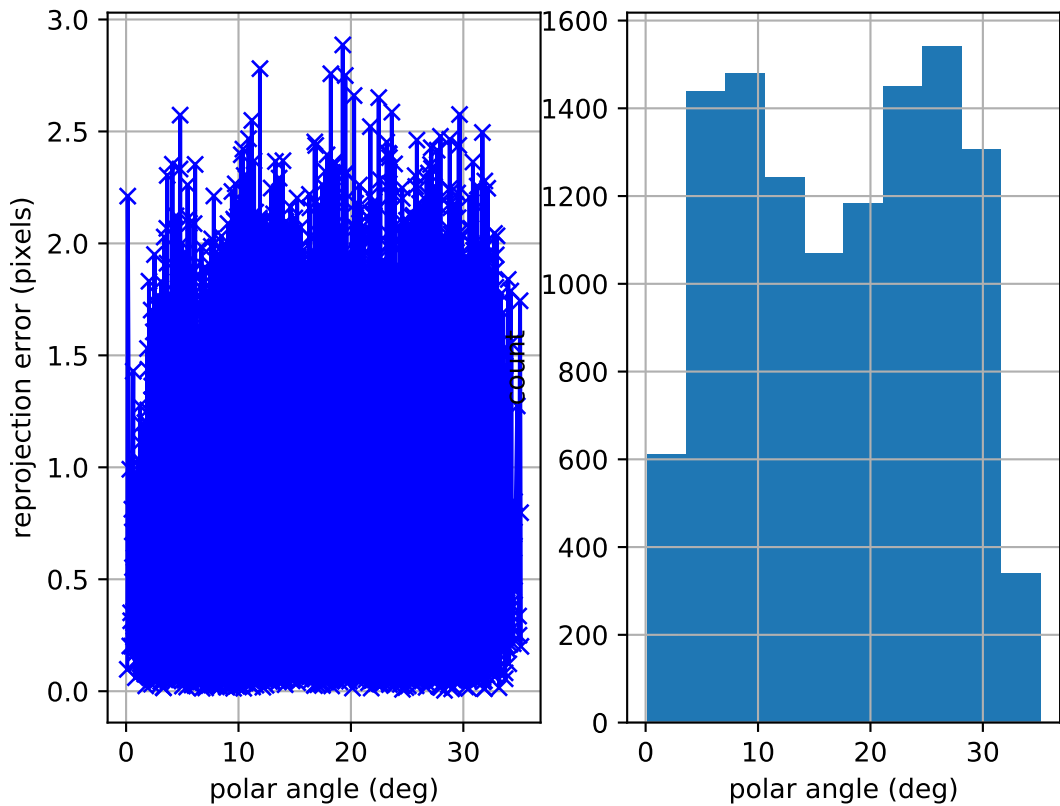
cam0: azimuthal error



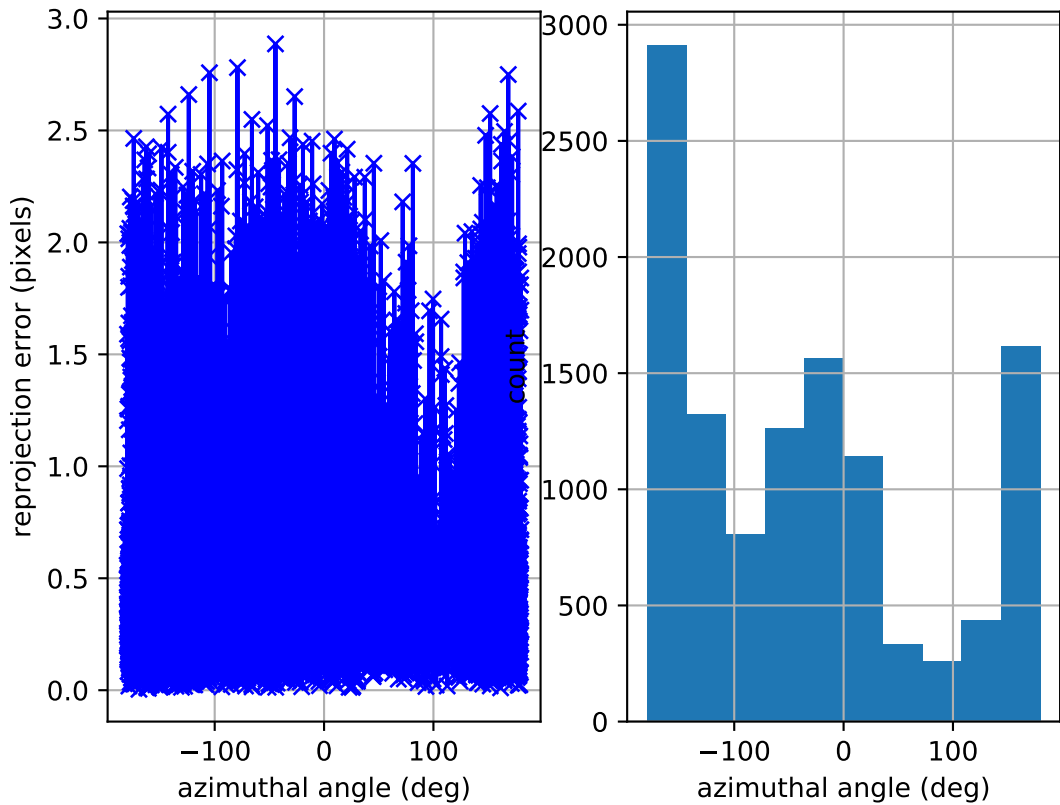
cam0: reprojection errors



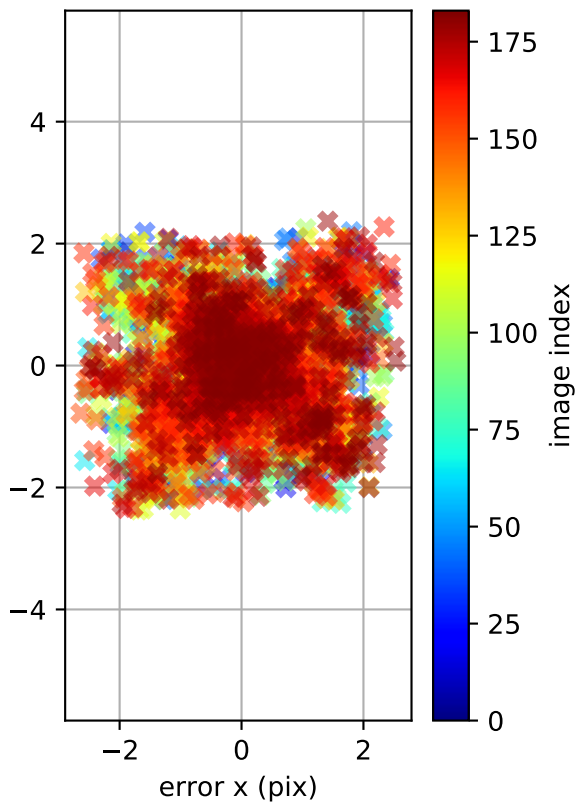
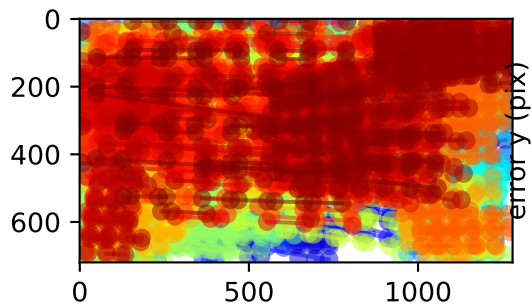
cam1: polar error



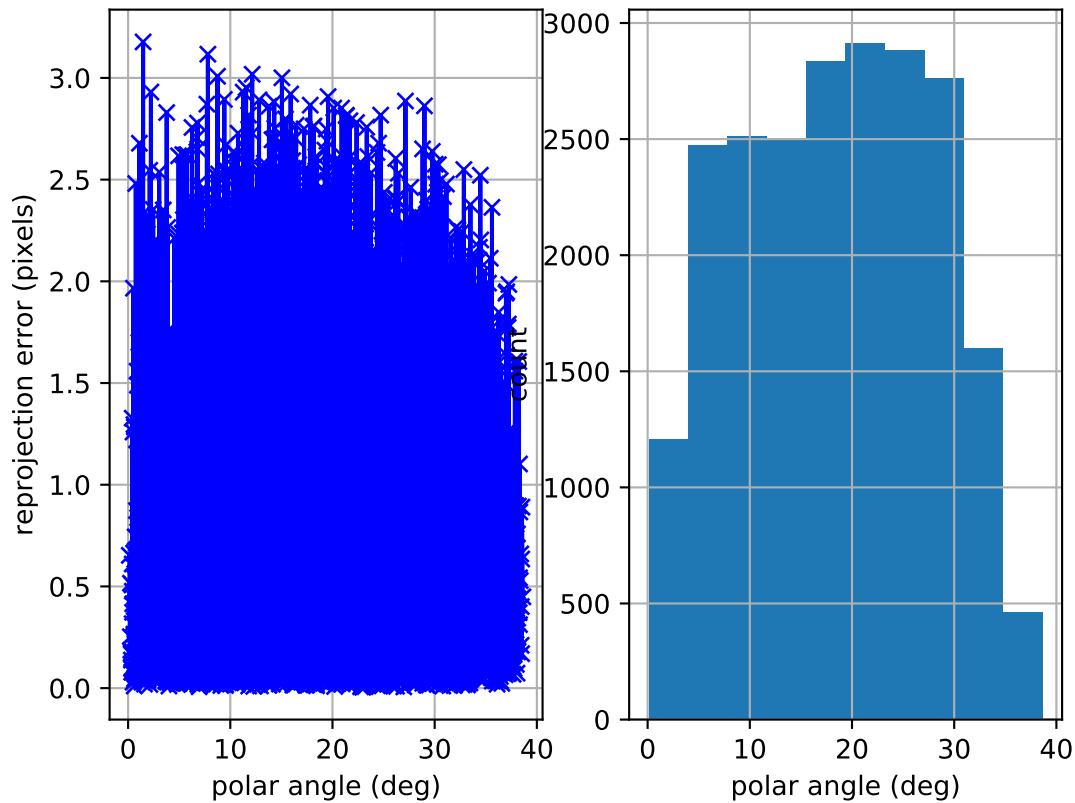
cam1: azimuthal error



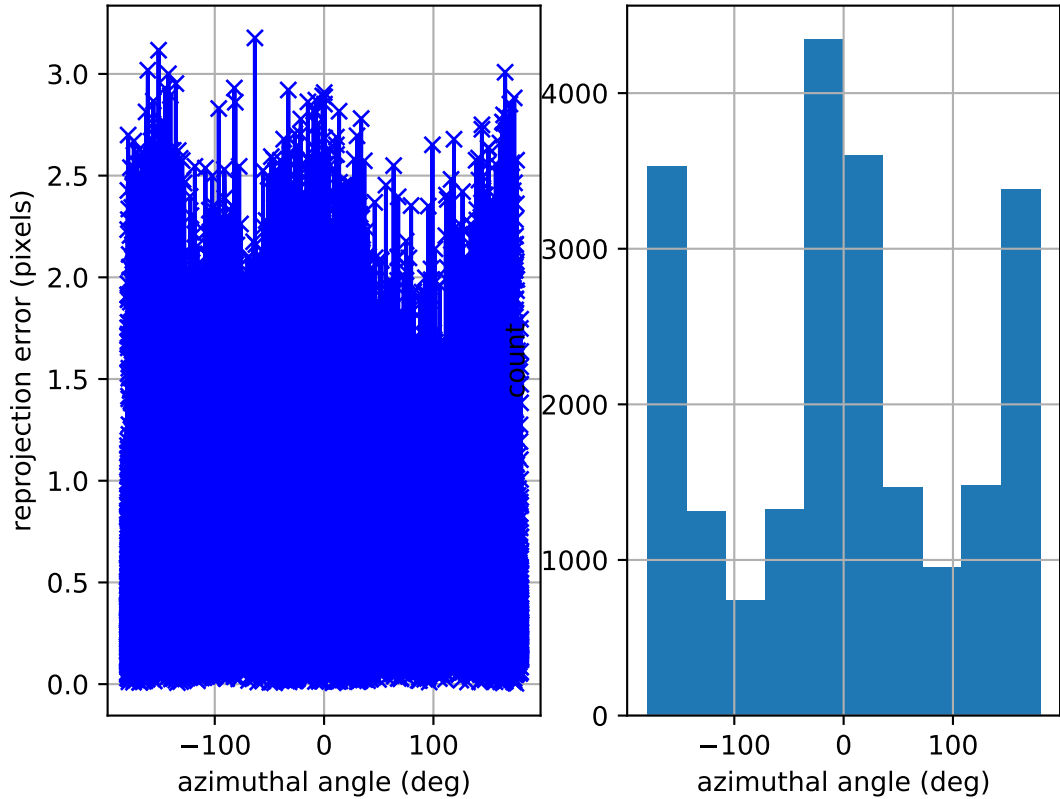
cam1: reprojection errors



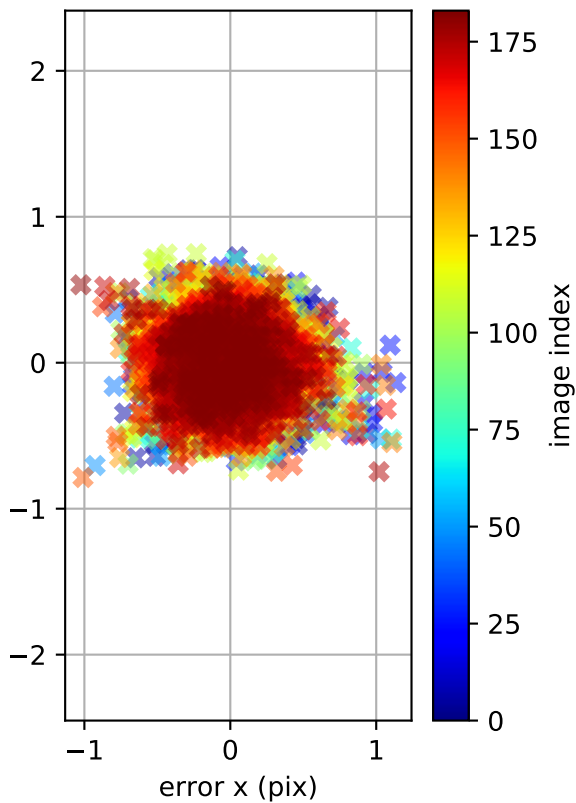
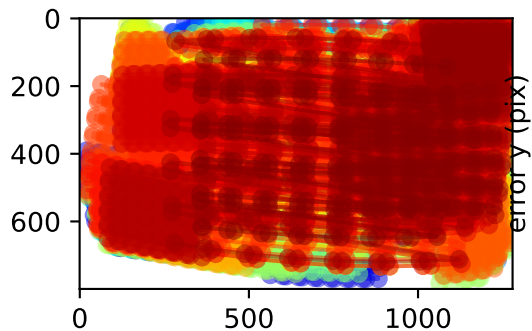
cam2: polar error



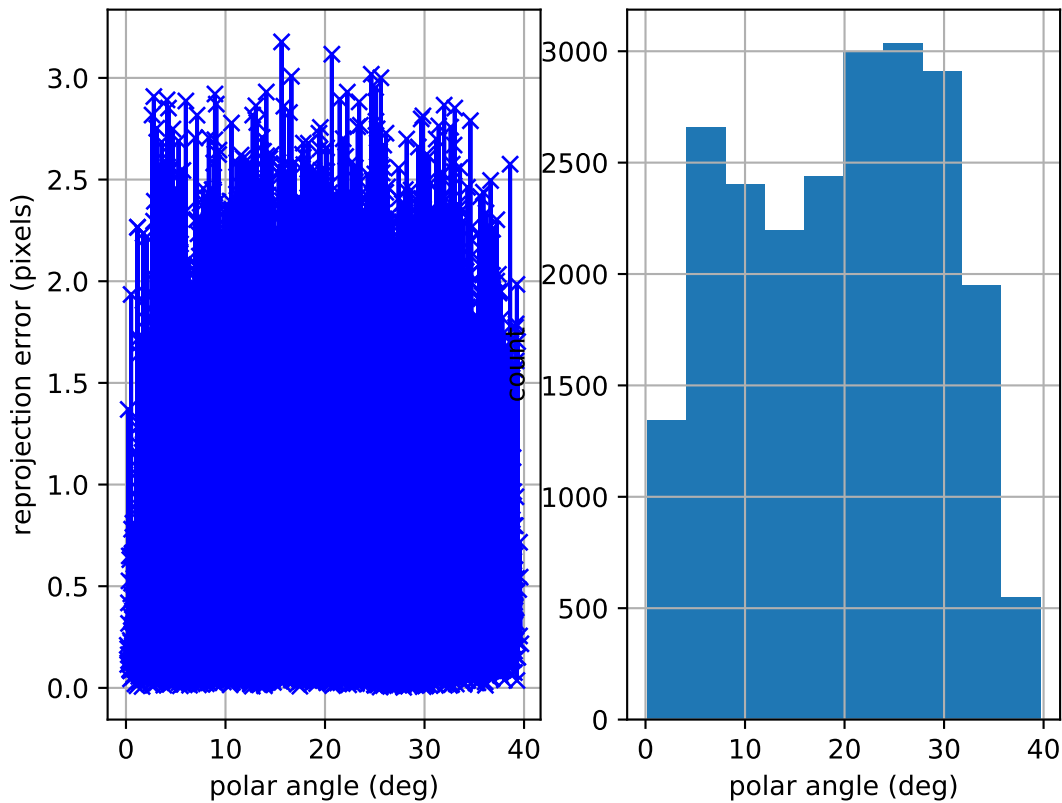
cam2: azimuthal error



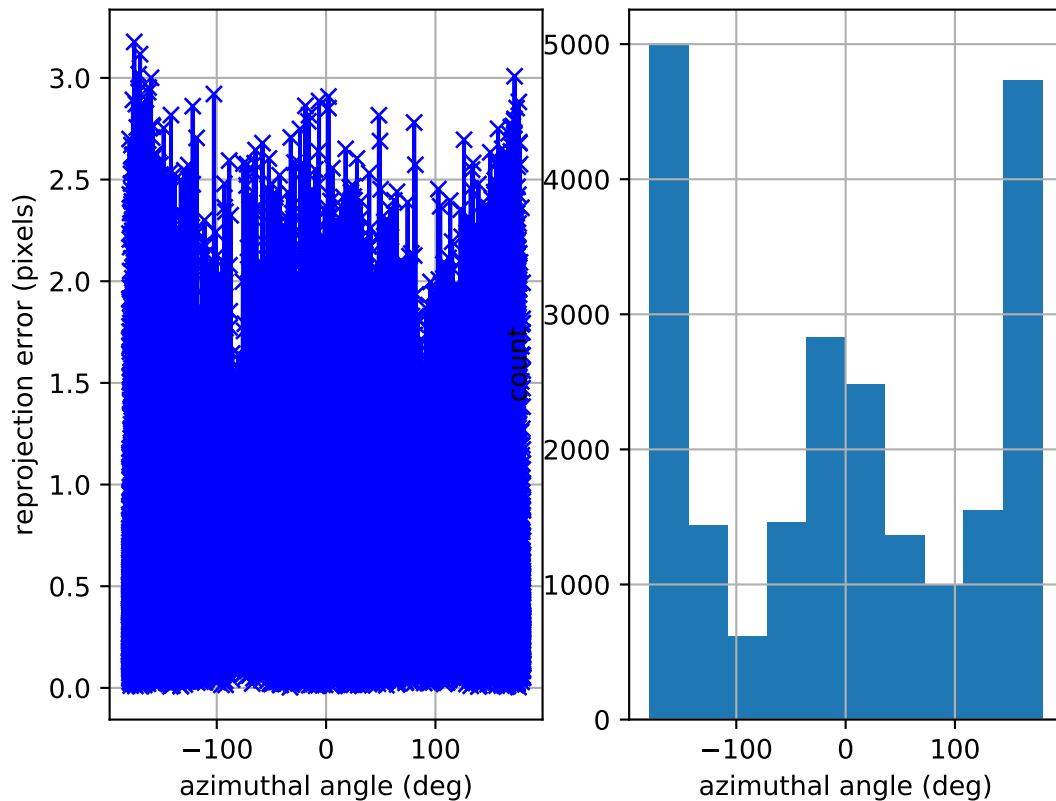
cam2: reprojection errors



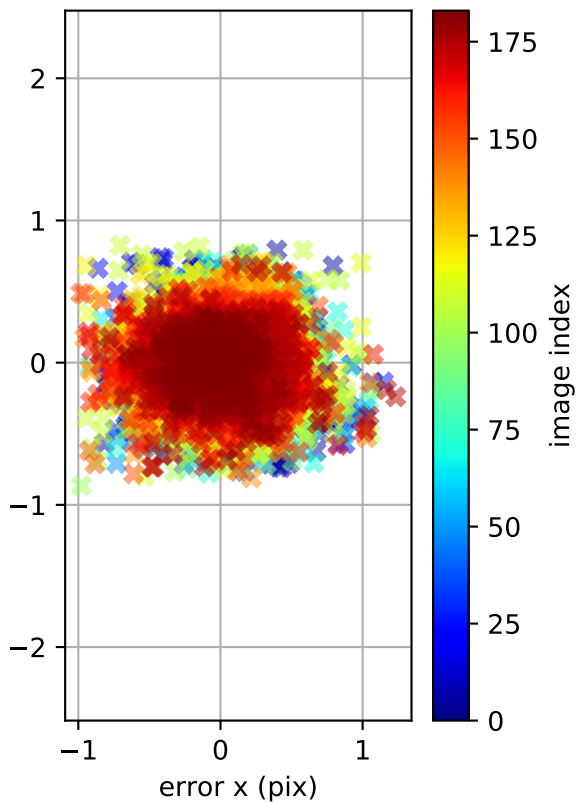
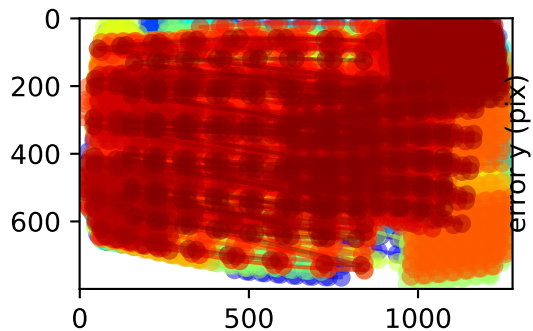
cam3: polar error



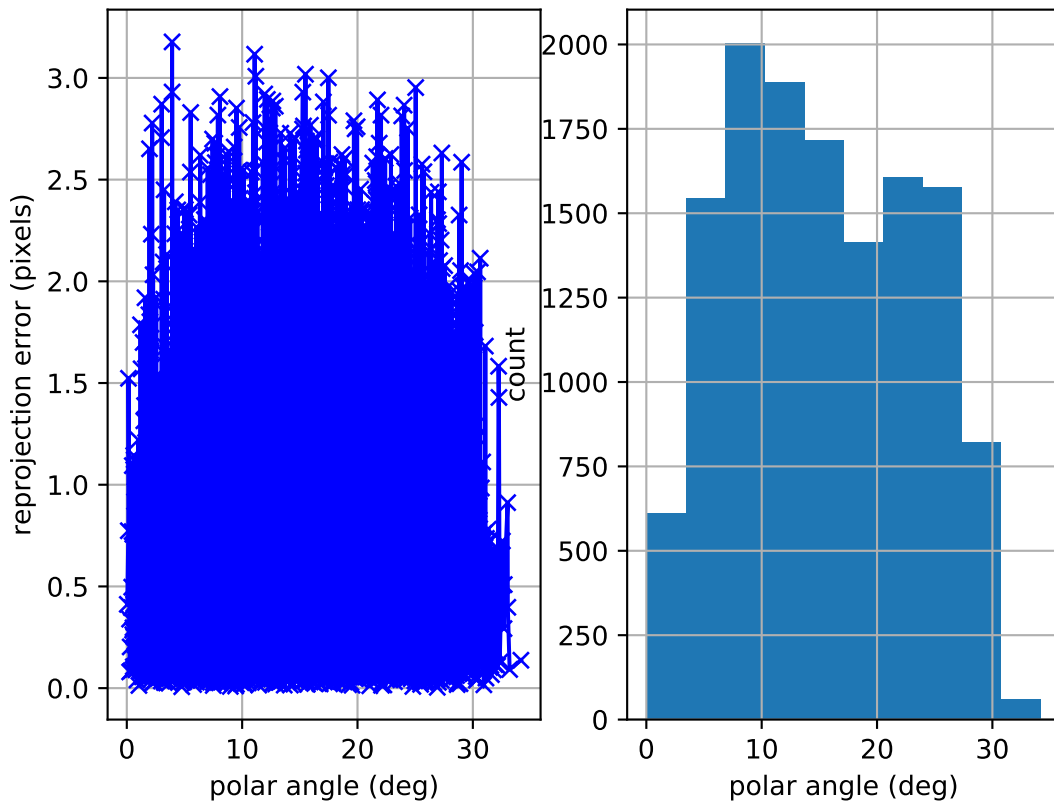
cam3: azimuthal error



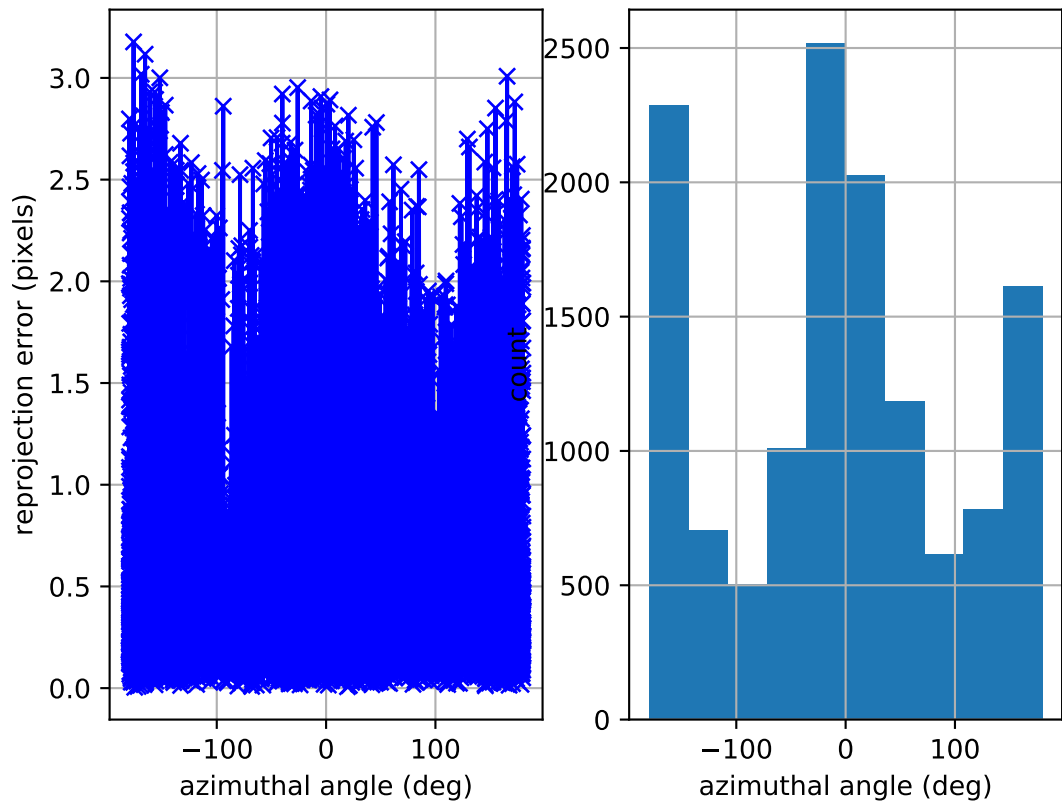
cam3: reprojection errors



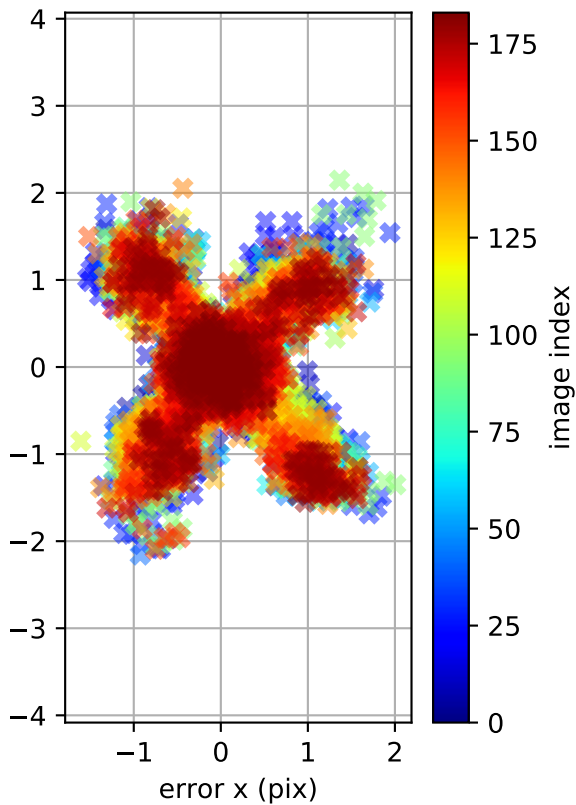
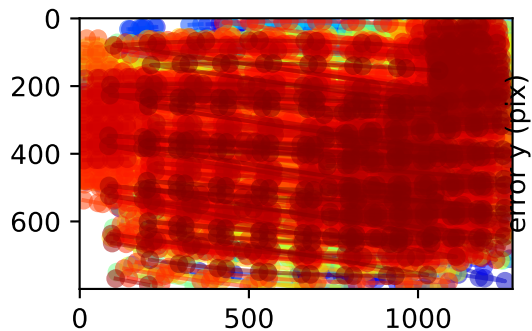
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

