

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04676935 0.08173436 0.00005151 -0.00065591] +- [0.00104674 0.00235368 0.0000782 0.00005762]

projection: [1032.02301691 1031.92283509 635.79846694 363.79830416] +- [0.12254068 0.12402816 0.00785501 0.12361702]

reprojection error: [0.000159, -0.000084] +- [0.350012, 0.331431]

cam1 (/prophesee/right/events):

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

distortion: [-0.05309921 0.08344803 0.0010687 0.00028115] +- [0.00105799 0.00239943 0.00007804 0.000057]

projection: [1031.49412912 1031.36825419 637.21356149 365.77813682] +- [0.12921503 0.12784965 0.00192819 0.10467252]

reprojection error: [0.000144, -0.000050] +- [0.478875, 0.442755]

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

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

distortion: [-0.39396683 0.158031 0.0000027 0.00053553] +- [0.00051668 0.00087636 0.00005626 0.00003719]

projection: [1058.17447808 1058.44701136 675.57043796 334.66060985] +- [0.09958626 0.10160433 0.00883502 0.22271689]

reprojection error: [0.000182, -0.000053] +- [0.212360, 0.192125]

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

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

distortion: [-0.3937252 0.155154 -0.00016655 0.00115598] +- [0.00047201 0.00076824 0.0000575 0.00003806]

projection: [1053.2183778 1053.7504045 672.97896171 327.64069848] +- [0.0987601 0.09834436 0.01609245 0.21796785]

reprojection error: [0.000182, -0.000112] +- [0.223557, 0.195907]

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

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

distortion: [-0.41735219 0.19227106 0.00013879 -0.00000638] +- [0.00082961 0.00210651 0.00006058 0.00004256]

projection: [1264.56332598 1264.60474381 653.87450245 366.6287892] +- [0.1116869 0.10872203 0.00945873 0.06480265]

reprojection error: [0.000036, -0.000038] +- [0.237783, 0.239913]

baseline T_1_0:

q: [-0.00073096 0.00194274 -0.00026879 0.99999781] +- [0.00007319 0.00004041 0.0000408]

t: [-0.12024336 0.00093071 -0.00031356] +- [0.0000267 0.0000265 0.00010324]

baseline T_2_1:

q: [-0.00045546 -0.00287143 -0.00521593 0.99998217] +- [0.00027025 0.00003704 0.0000384]

t: [0.12014621 0.06920065 0.00437771] +- [0.0000238 0.00002368 0.0000938]

baseline T_3_2:

q: [0.00006107 -0.0022131 0.00028668 0.99999751] +- [0.00031188 0.00003588 0.00003363]

t: [-0.12000993 -0.00009805 0.00087955] +- [0.00002001 0.00001977 0.00007814]

baseline T_4_3:

q: [0.00183254 0.00460027 0.00033508 0.99998768] +- [0.00023901 0.00003532 0.00003354]

t: [0.08883028 0.00618187 0.00321304] +- [0.00001869 0.0000181 0.00007704]

Target configuration

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Type: aprilgrid

Tags:

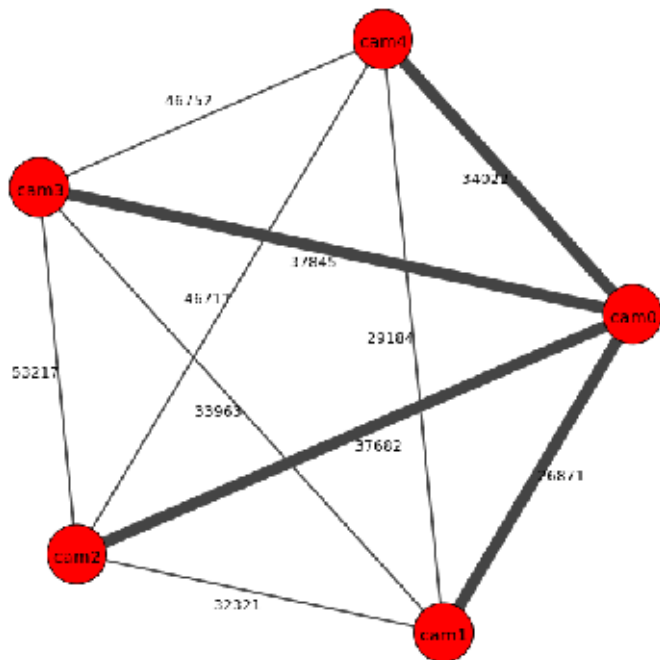
Rows: 5

Cols: 7

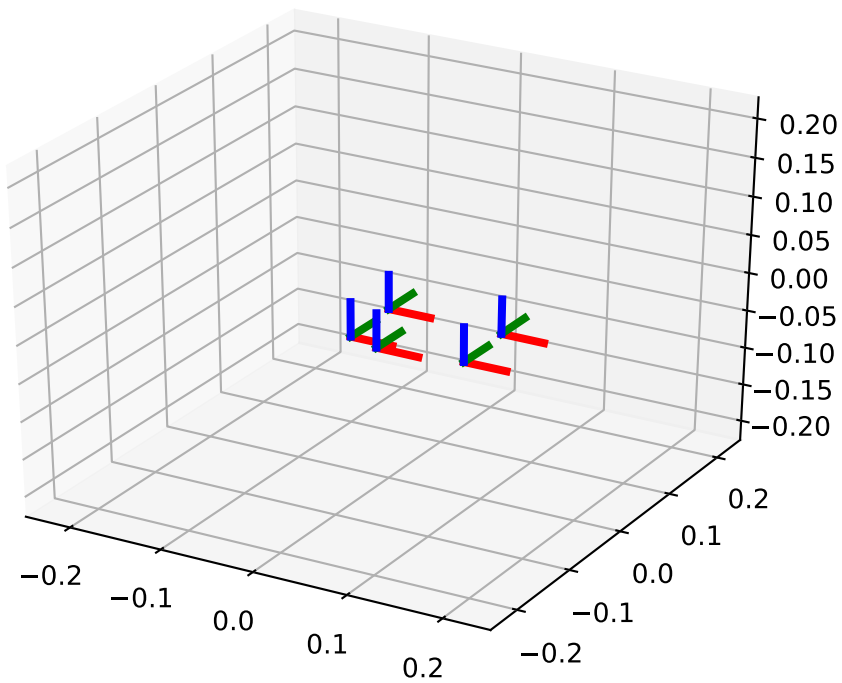
Size: 0.04 [m]

Spacing 0.01 [m]

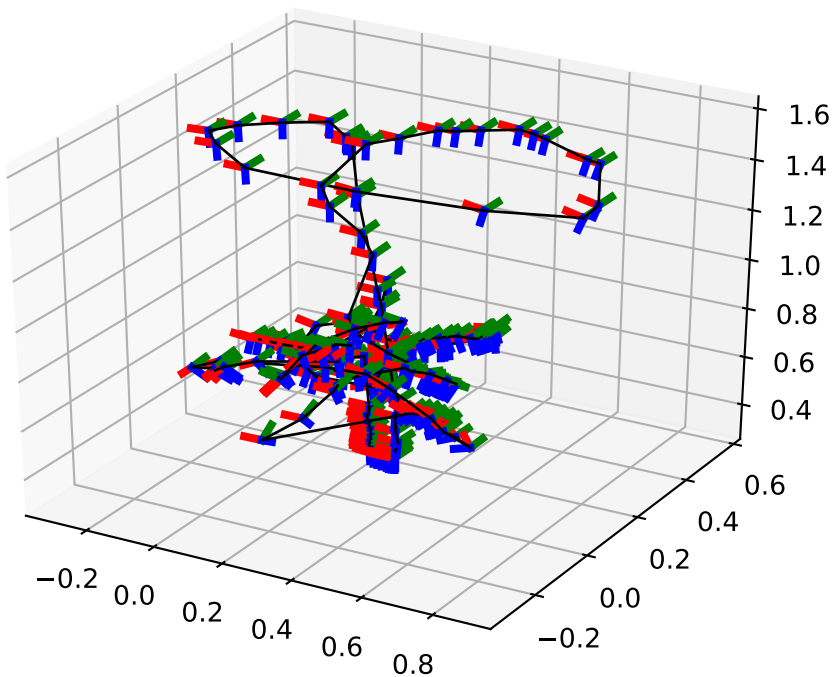
Inter-camera observations graph (edge weight=#mutual obs.)



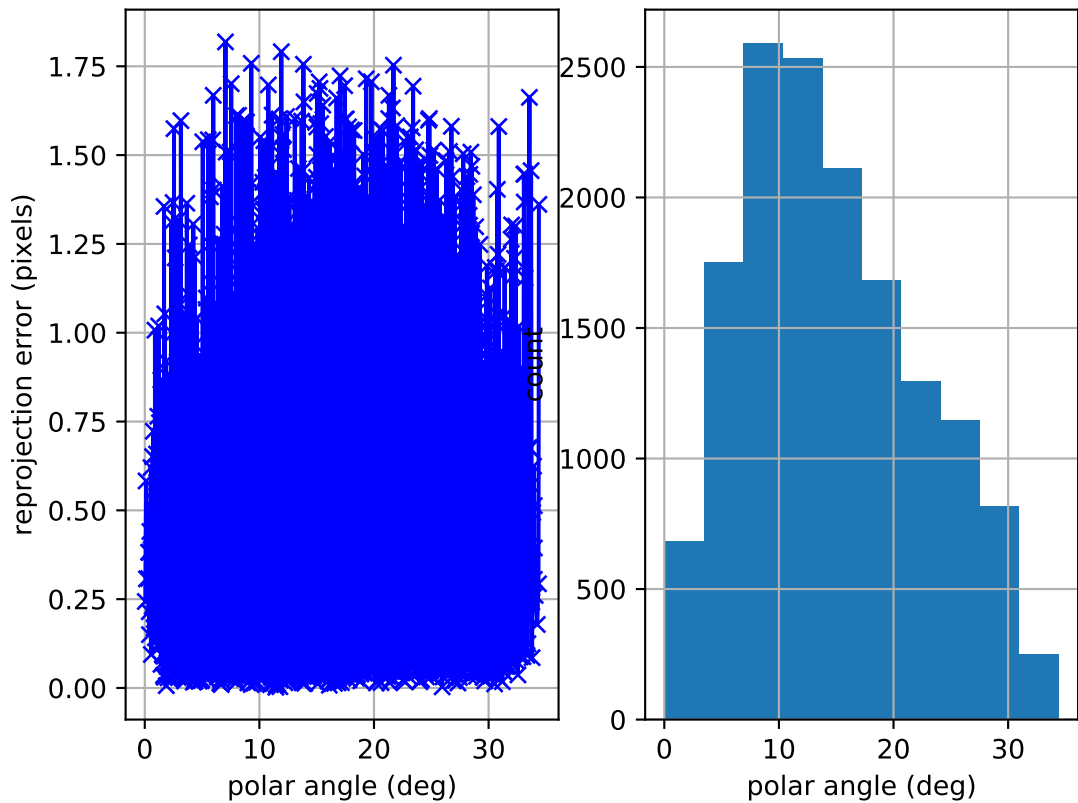
camera system



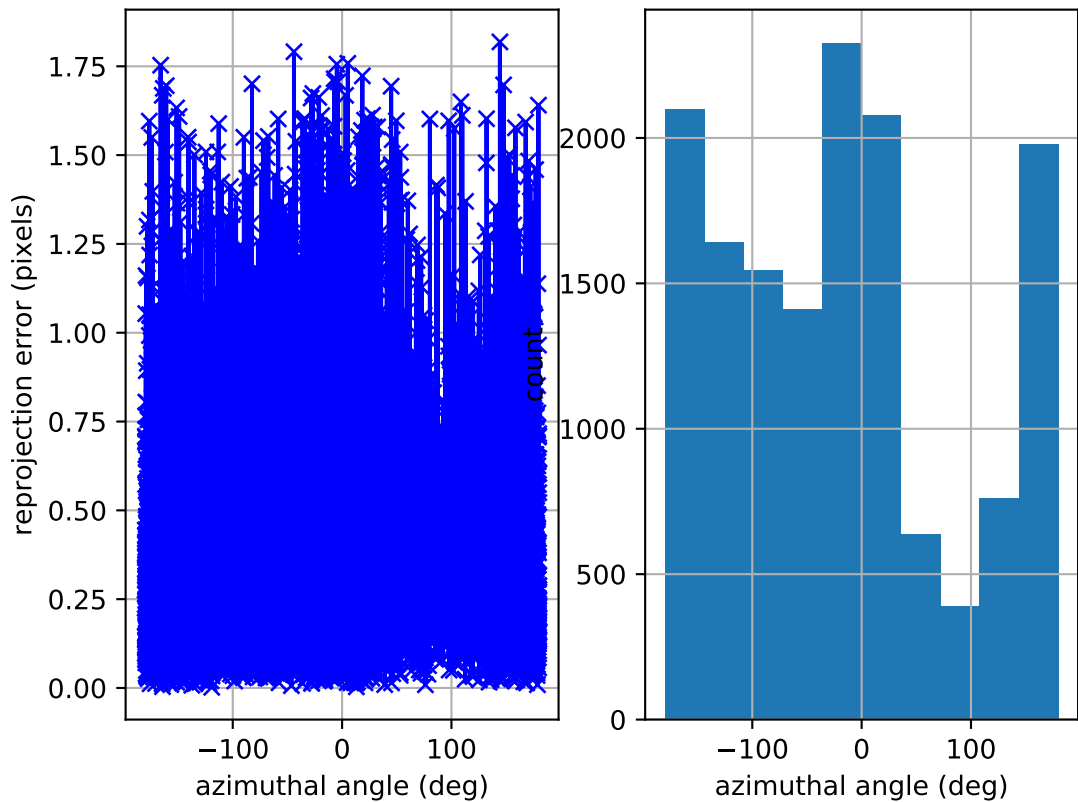
cam0: estimated poses



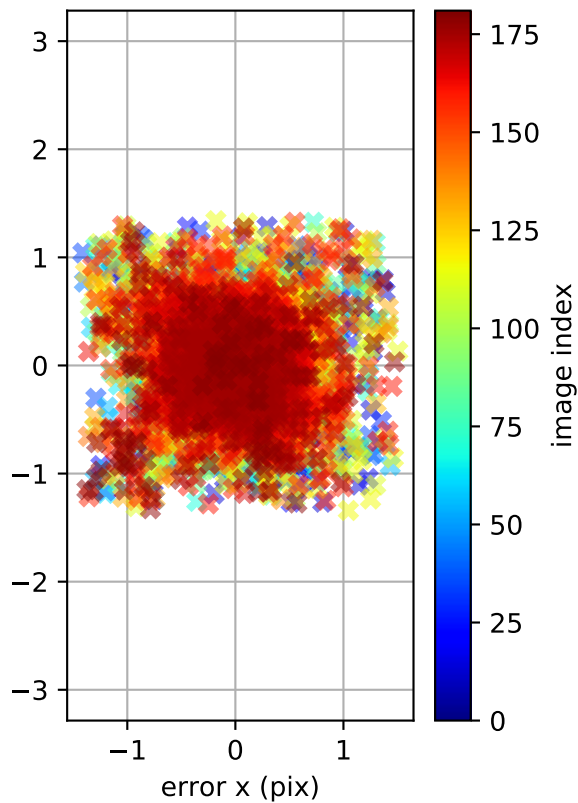
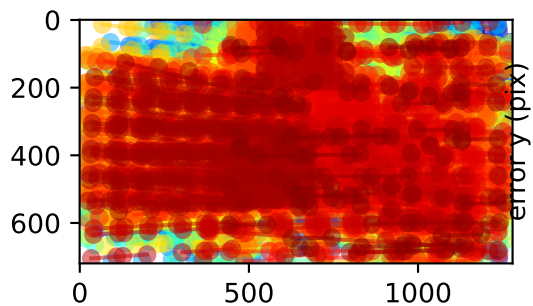
cam0: polar error



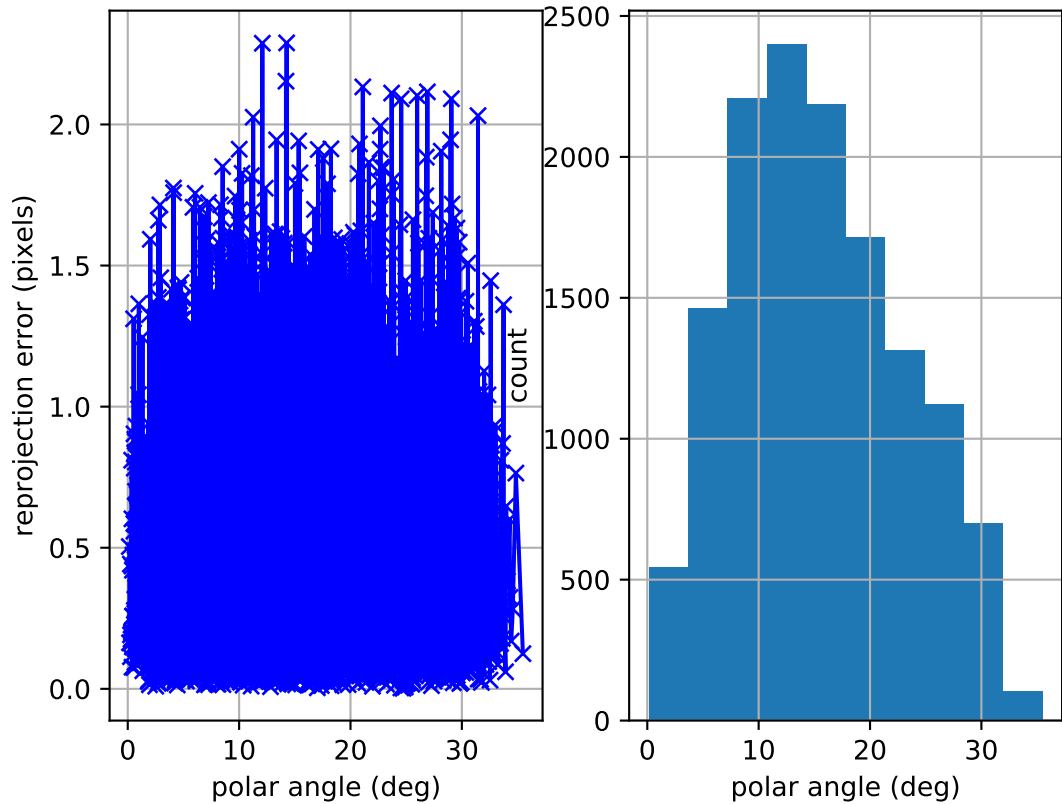
cam0: azimuthal error



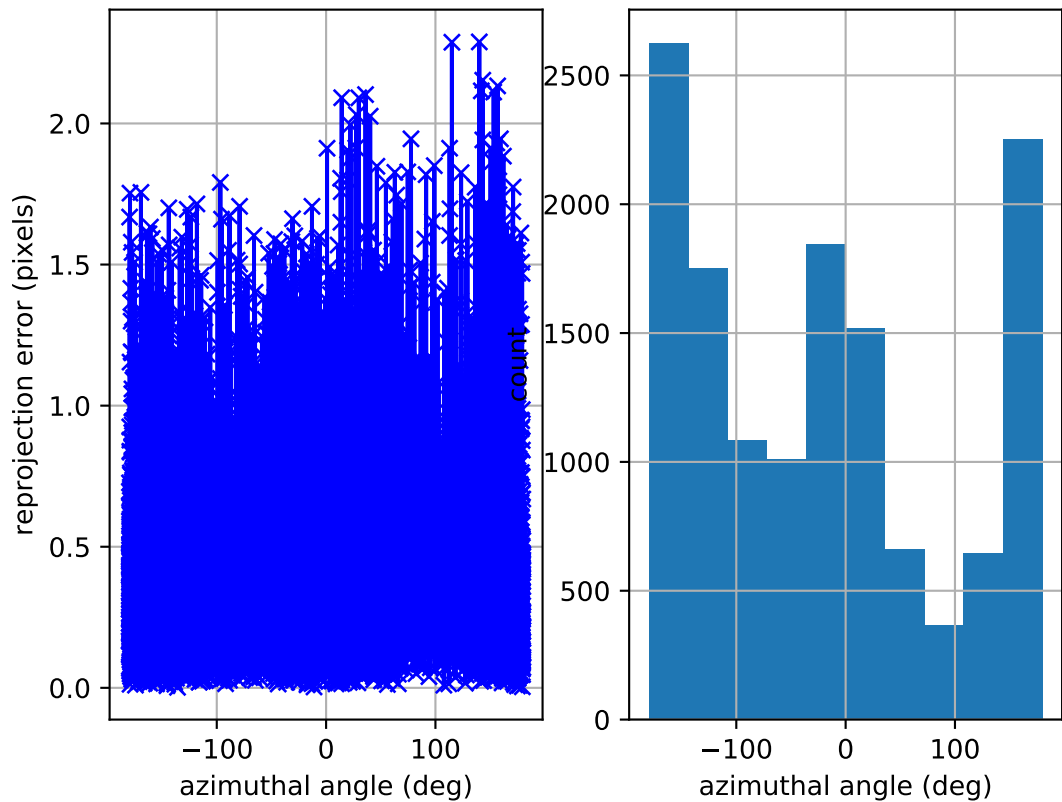
cam0: reprojection errors



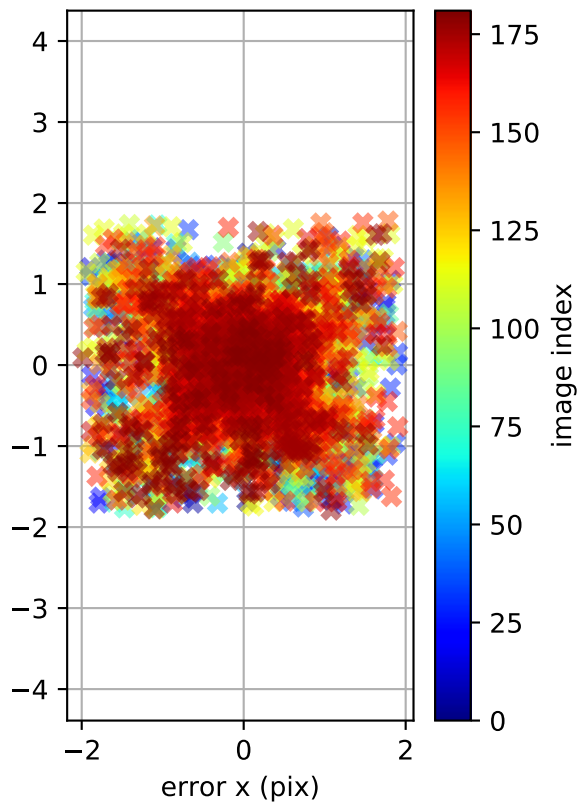
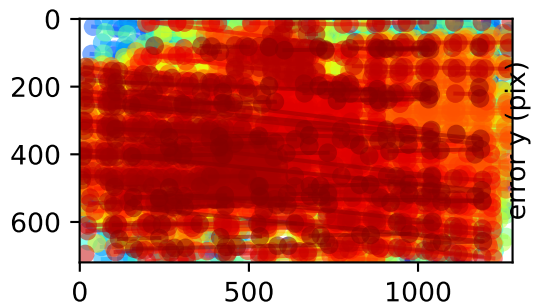
cam1: polar error



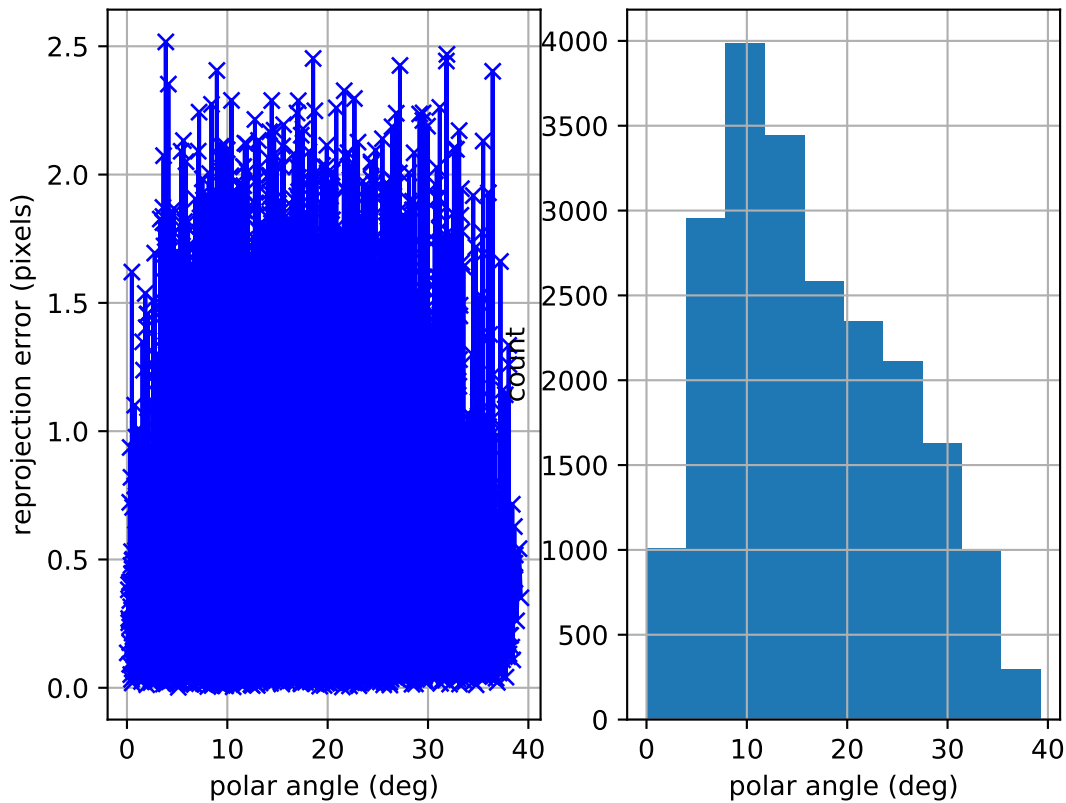
cam1: azimuthal error



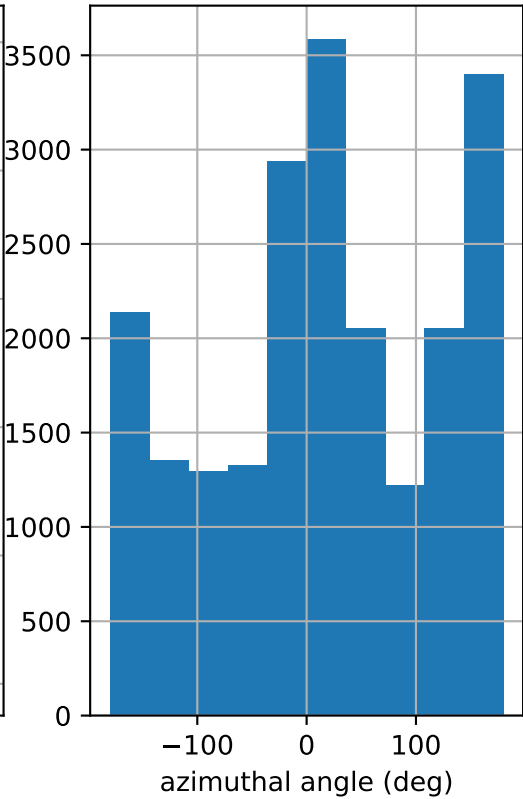
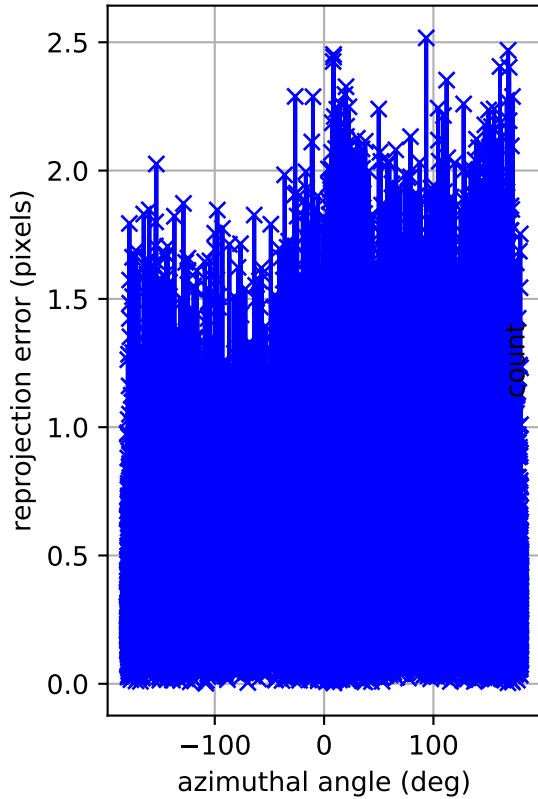
cam1: reprojection errors



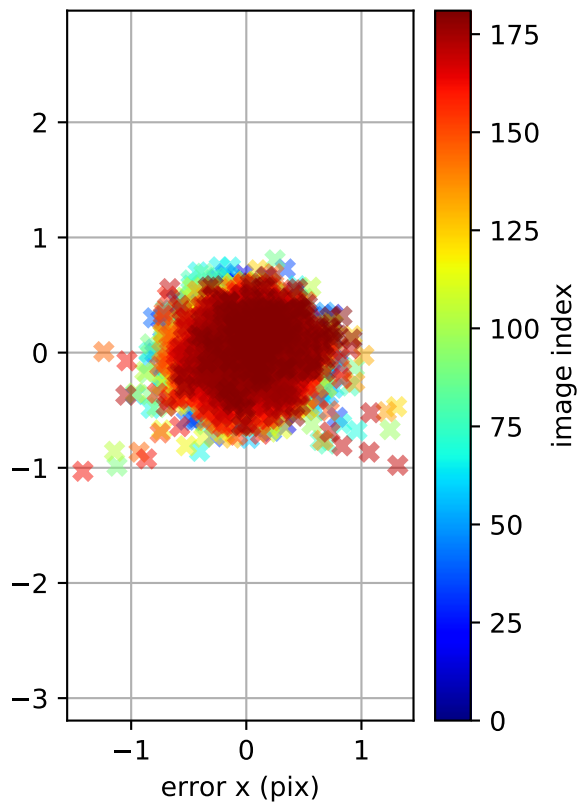
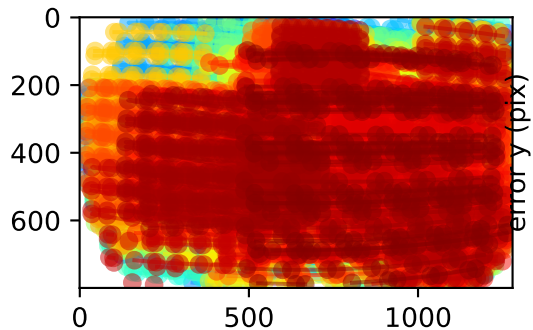
cam2: polar error



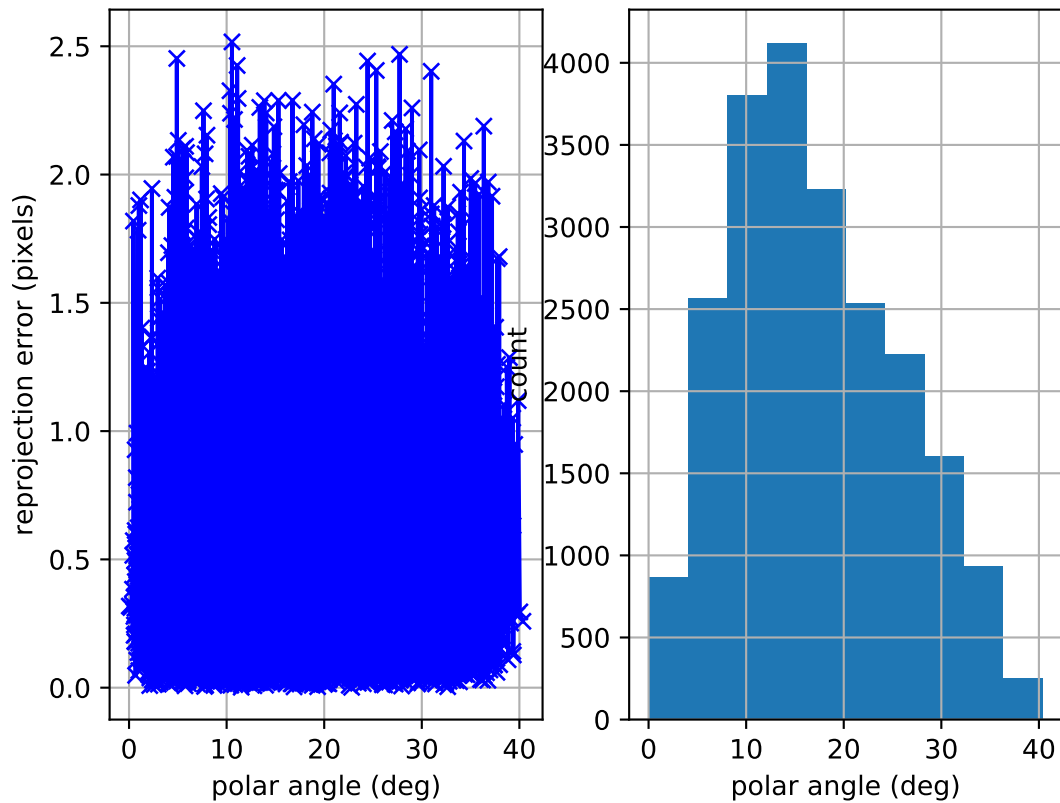
cam2: azimuthal error



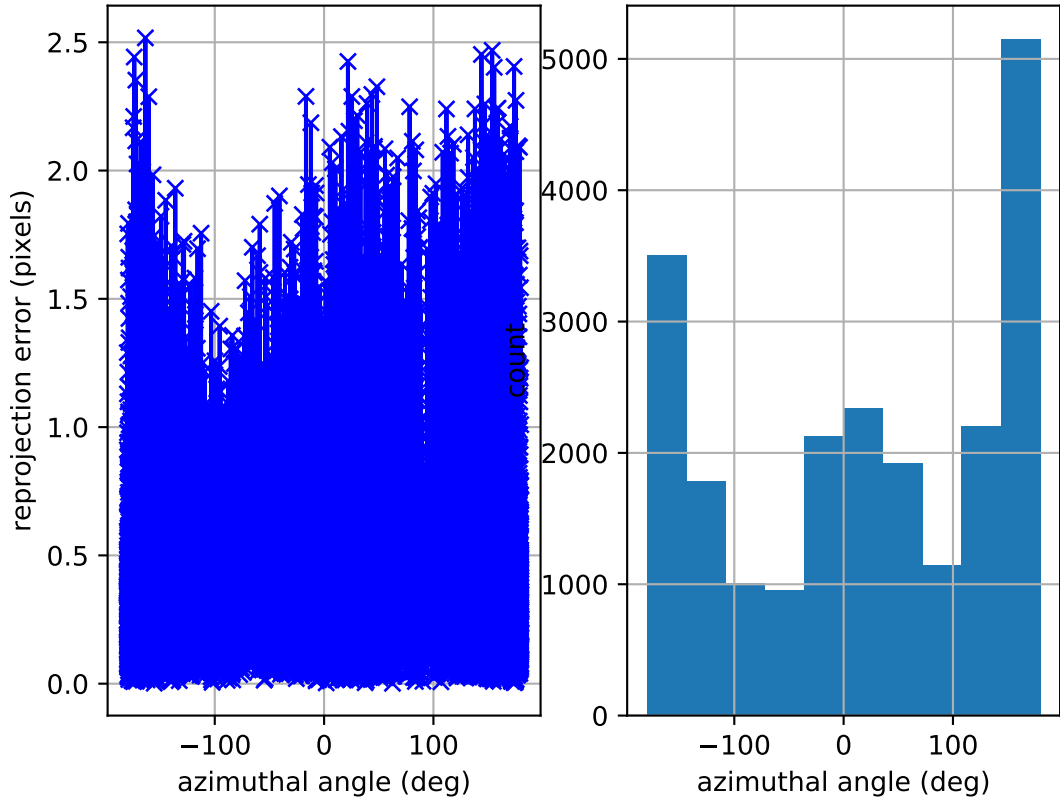
cam2: reprojection errors



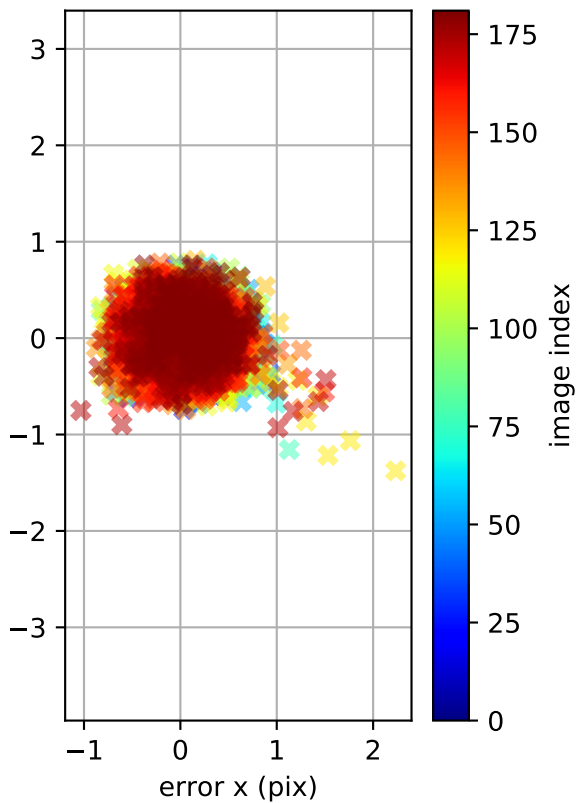
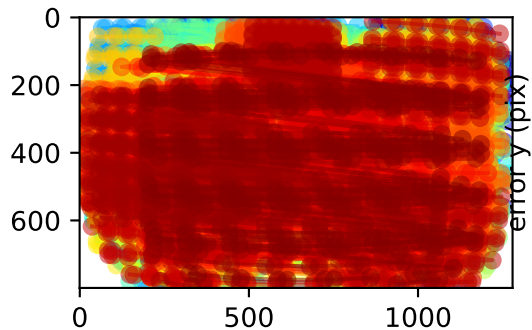
cam3: polar error



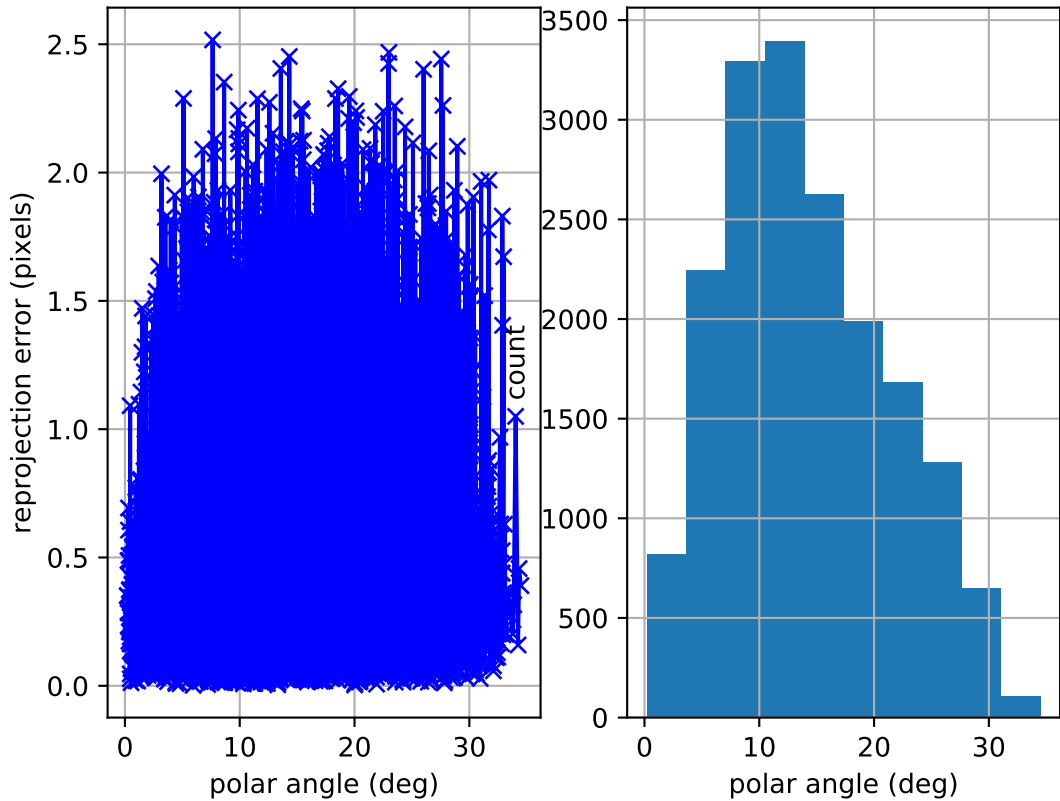
cam3: azimuthal error



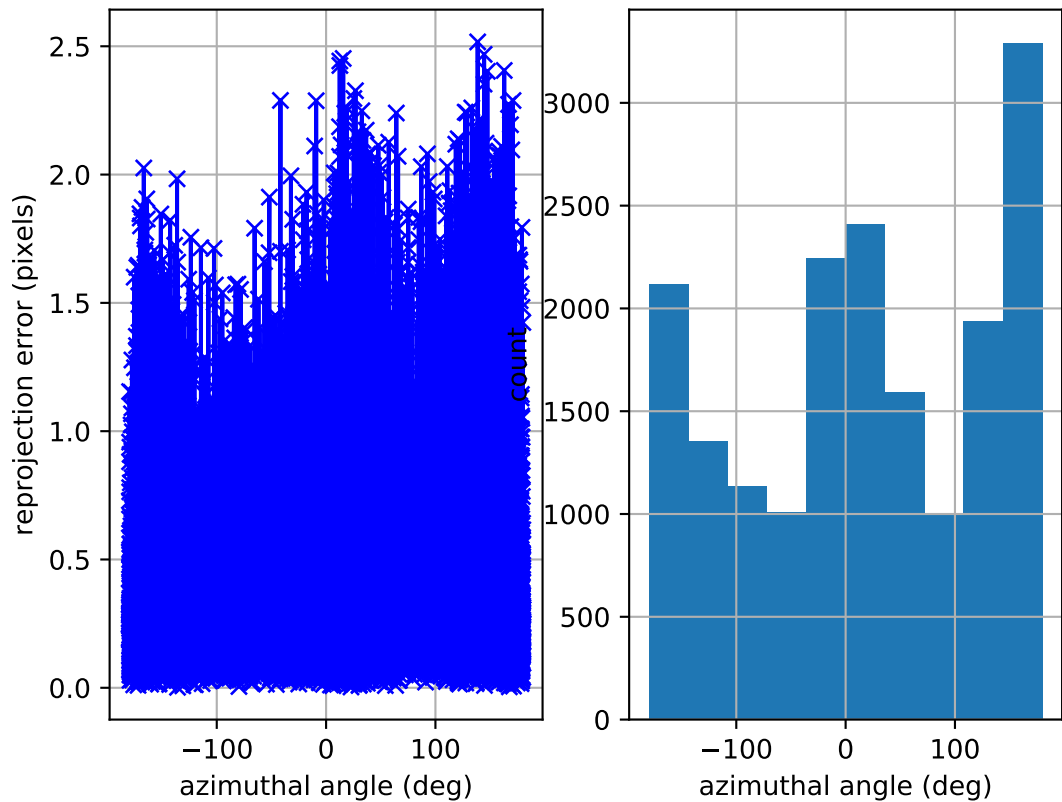
cam3: reprojection errors



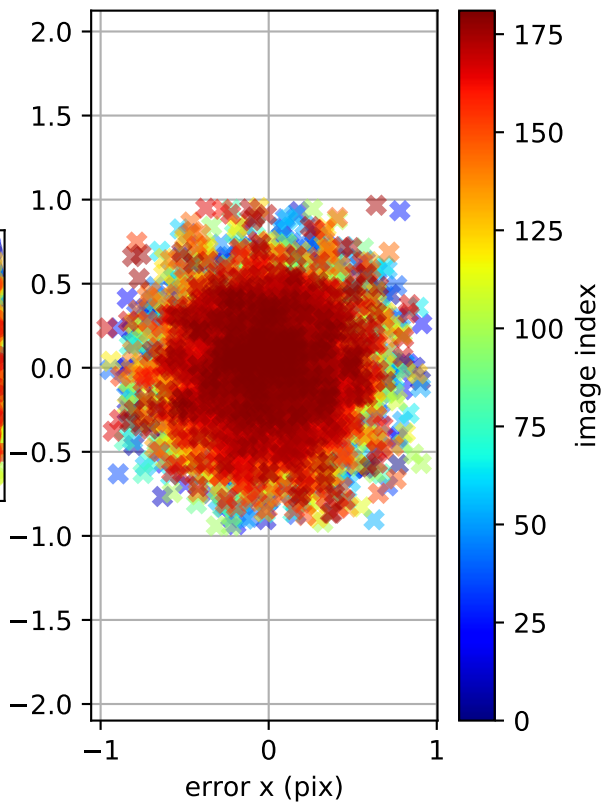
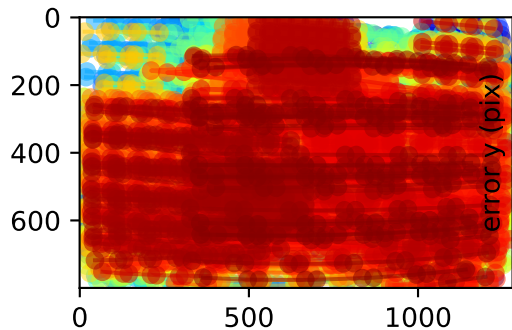
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

