

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04730162 0.08000713 0.00045231 -0.00062545] +- [0.00098487 0.00207394 0.00009086 0.00007562]

projection: [1032.17190373 1032.19800187 635.97300475 365.80364233] +- [0.1287226 0.13494064 0.00799185 0.14985896]

reprojection error: [-0.000032, -0.000050] +- [0.376288, 0.325868]

cam1 (/prophesee/right/events):

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

distortion: [-0.0535153 0.08145484 0.00139301 0.00035839] +- [0.00097953 0.00211997 0.00008888 0.00008271]

projection: [1031.31292827 1031.54983795 638.53148226 368.44197347] +- [0.12839216 0.13323847 0.01087187 0.11552134]

reprojection error: [-0.000001, -0.000069] +- [0.434294, 0.405806]

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

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

distortion: [-0.39466628 0.15863721 -0.00032256 0.00042768] +- [0.00054927 0.00095178 0.00006369 0.0000489]

projection: [1058.80165879 1059.12973043 676.48003889 337.28600203] +- [0.11790314 0.12352331 0.015914 0.18382266]

reprojection error: [0.000003, -0.000105] +- [0.210571, 0.164777]

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

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

distortion: [-0.39487291 0.15480927 -0.00038379 0.00082391] +- [0.00050316 0.00078558 0.00006279 0.00005294]

projection: [1053.74726089 1054.41359713 675.10750417 329.04691339] +- [0.12401221 0.12834499 0.00926163 0.18805087]

reprojection error: [-0.000006, -0.000044] +- [0.212893, 0.164688]

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

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

distortion: [-0.41275073 0.1797212 0.00016433 -0.00025056] +- [0.00076405 0.00180388 0.00006619 0.00005185]

projection: [1262.48038393 1262.66408353 653.5584563 367.00943814] +- [0.1268454 0.13233828 0.00352205 0.05809598]

reprojection error: [-0.000089, -0.000112] +- [0.398326, 0.299414]

baseline T_1_0:

q: [-0.00104842 0.00233535 -0.00034797 0.99999666] +- [0.00017976 0.00005326 0.00003849]

t: [-0.12035265 0.00094334 -0.00057849] +- [0.00003572 0.00003423 0.00011294]

baseline T_2_1:

q: [-0.00051982 -0.00279165 -0.00525372 0.99998217] +- [0.00023261 0.00005148 0.00003649]

t: [0.12012157 0.06919627 0.00468778] +- [0.00003203 0.00003096 0.00011227]

baseline T_3_2:

q: [0.00062381 -0.00216125 0.00025189 0.99999744] +- [0.00027341 0.00004287 0.00003161]

t: [-0.12008824 -0.00008102 0.00084938] +- [0.00002702 0.00002425 0.00010807]

baseline T_4_3:

q: [0.00243446 0.00371077 0.00029798 0.99999011] +- [0.00021073 0.00003319 0.00003054]

t: [0.08872362 0.00611168 0.00202311] +- [0.00002414 0.00002278 0.00010351]

Target configuration

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Type: aprilgrid

Tags:

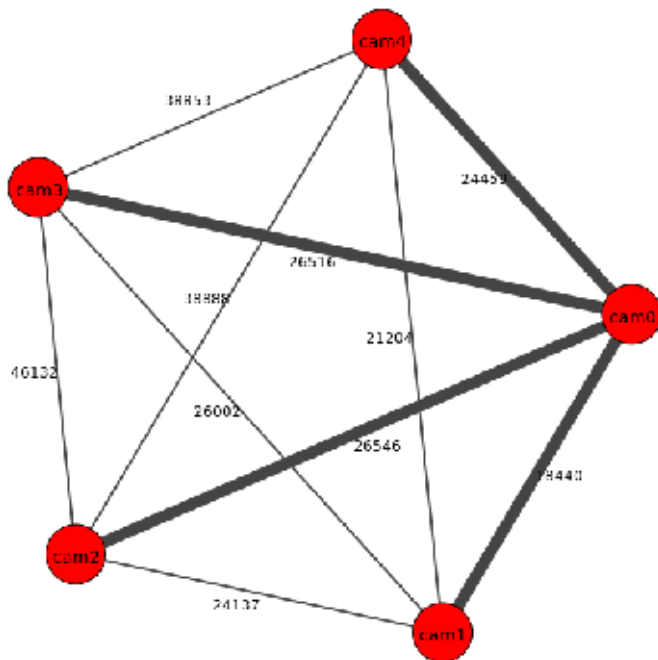
Rows: 5

Cols: 7

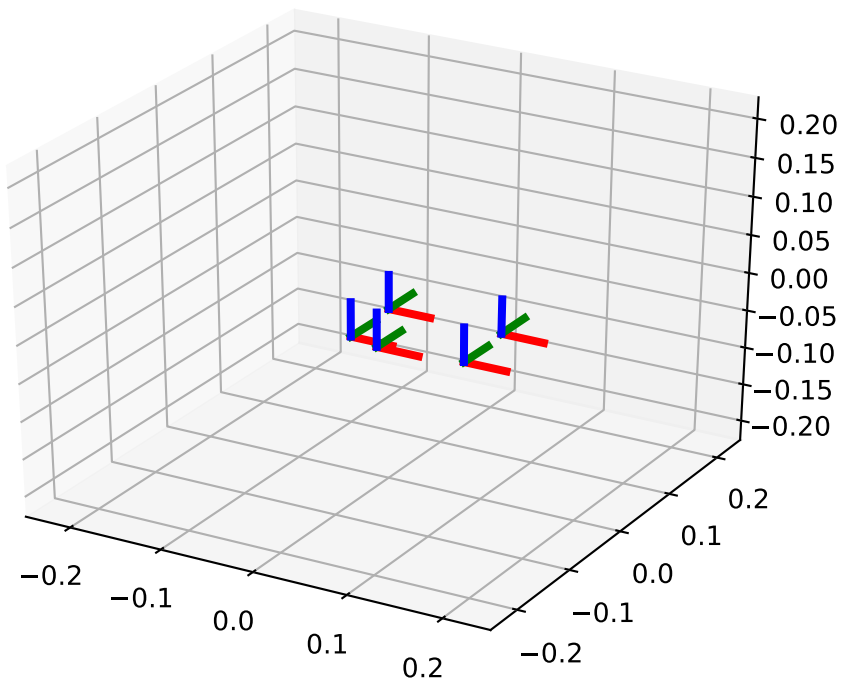
Size: 0.04 [m]

Spacing 0.01 [m]

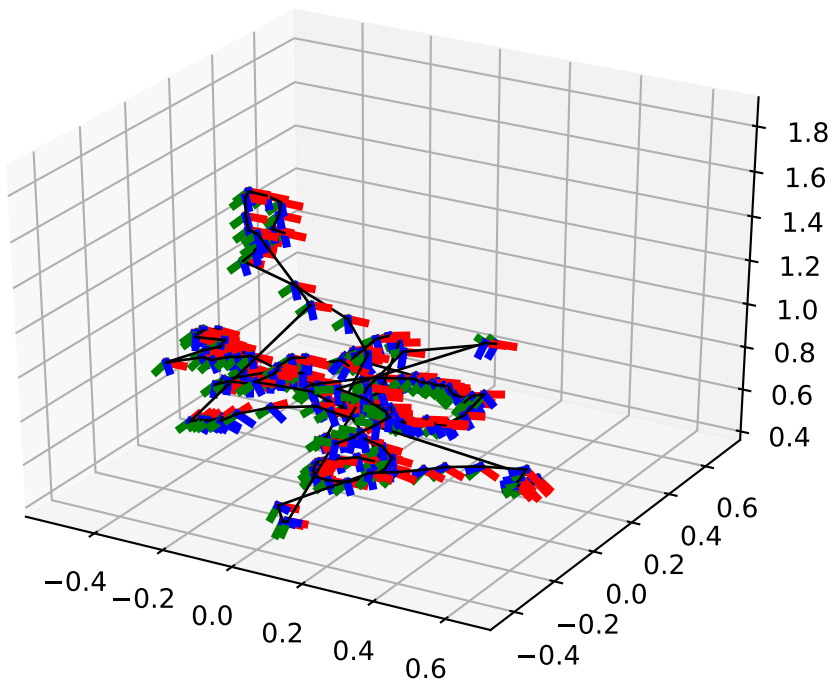
Inter-camera observations graph (edge weight=#mutual obs.)



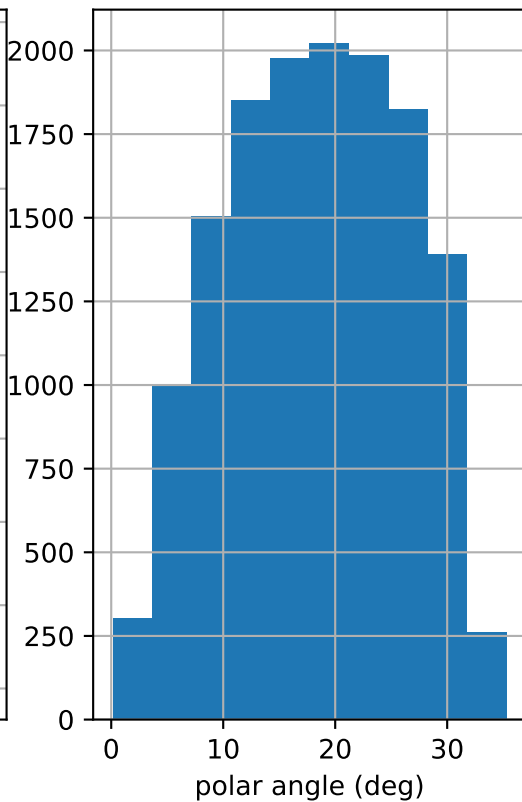
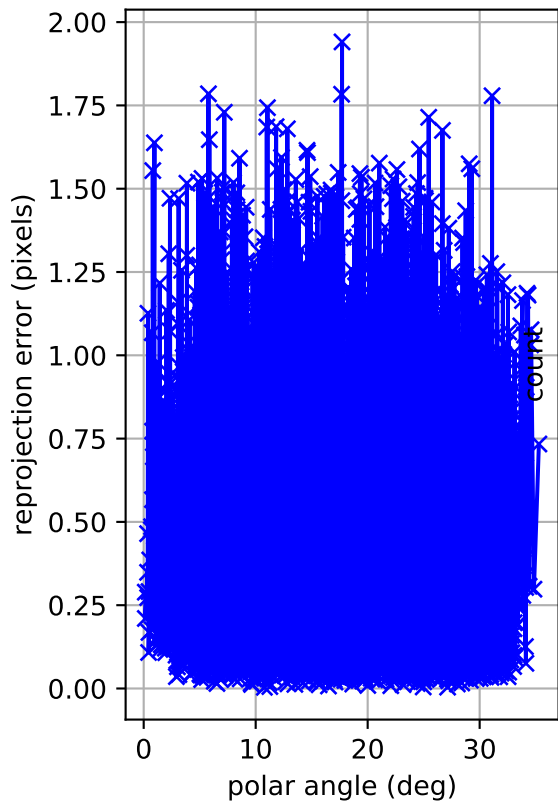
camera system



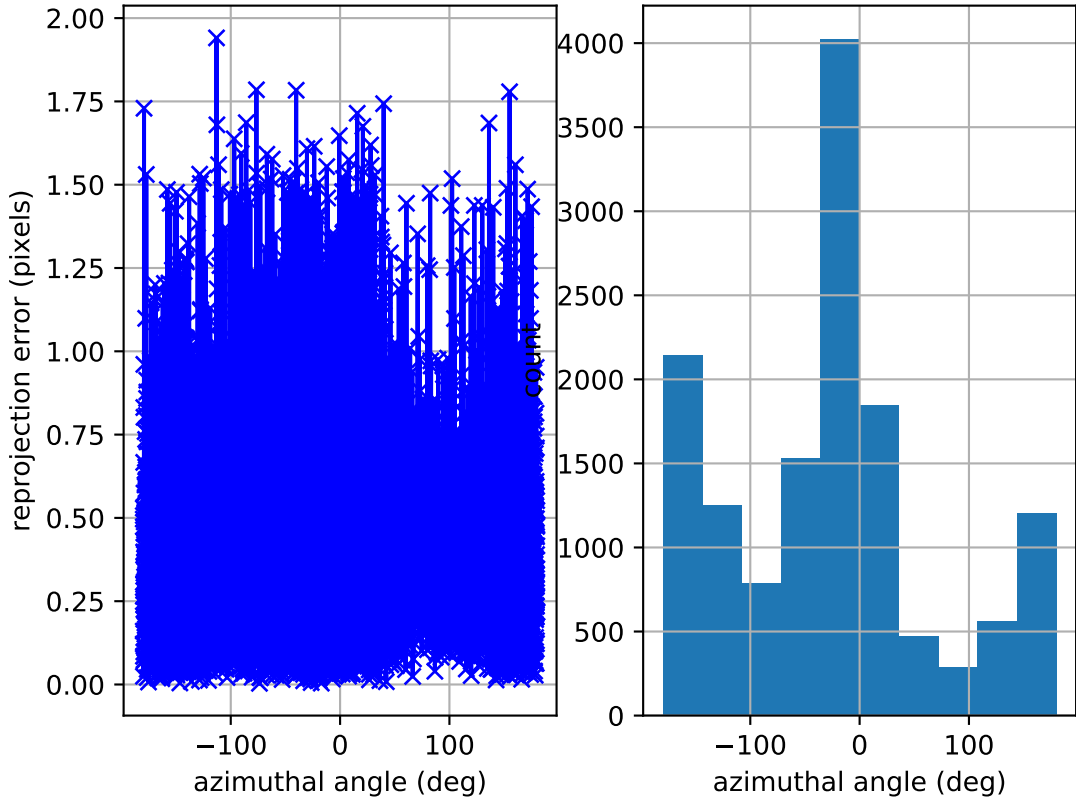
cam0: estimated poses



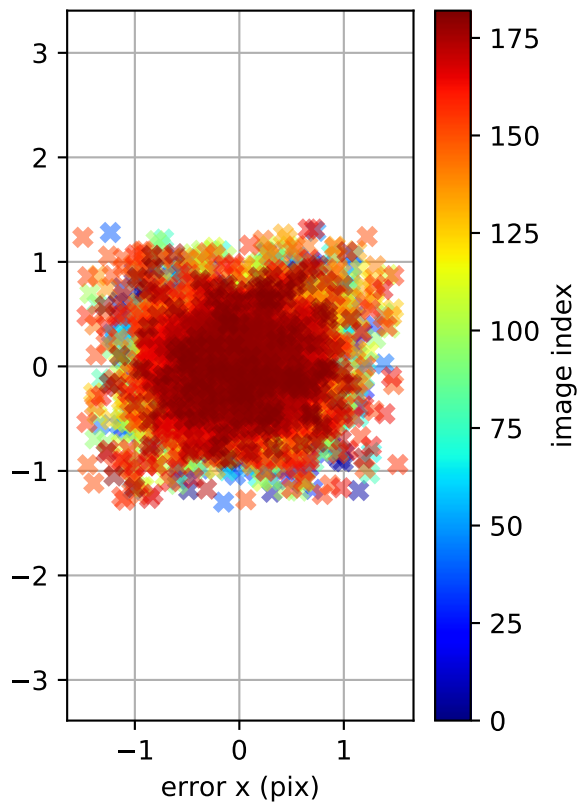
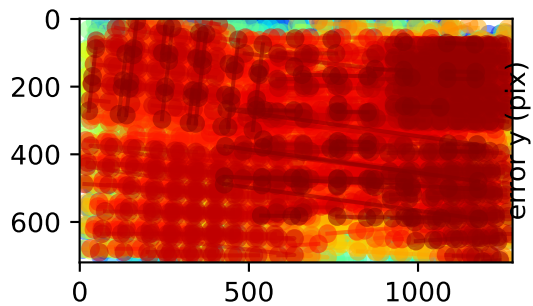
cam0: polar error



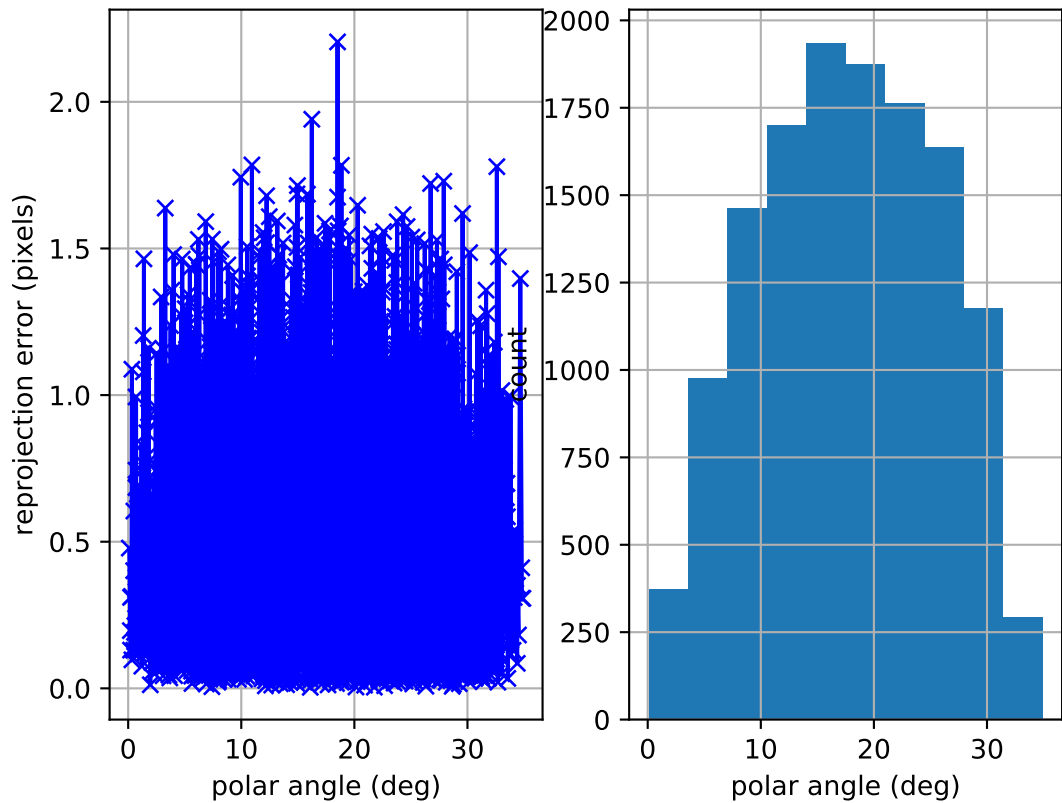
cam0: azimuthal error



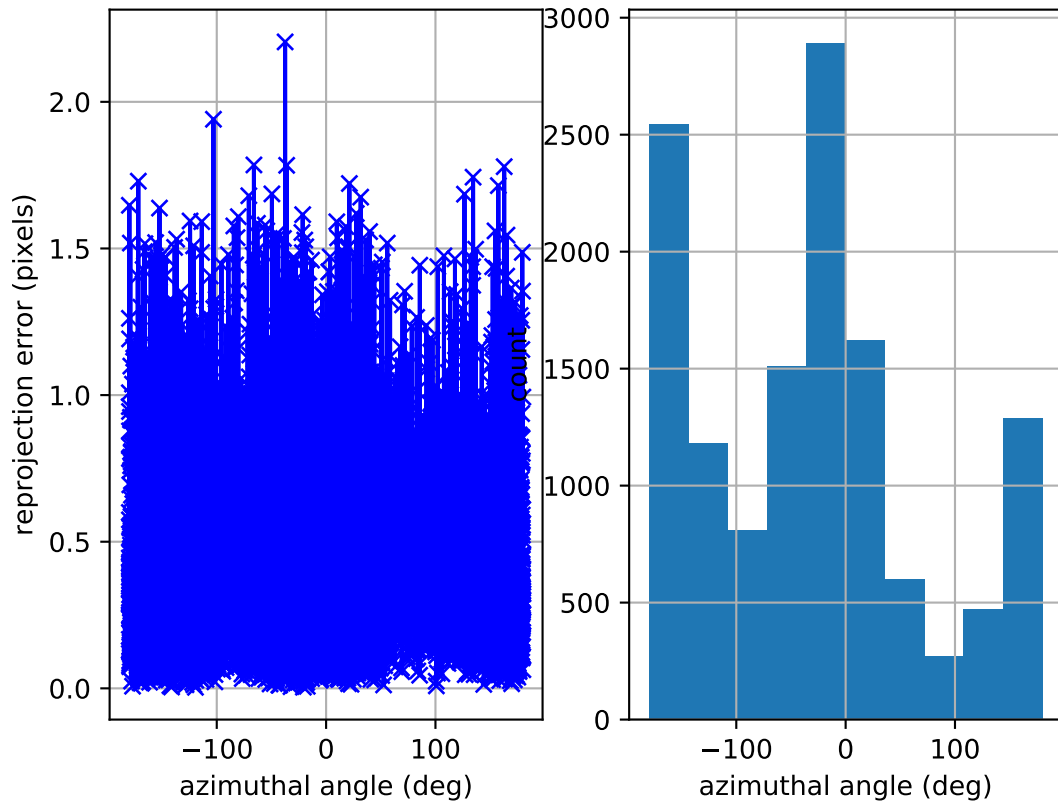
cam0: reprojection errors



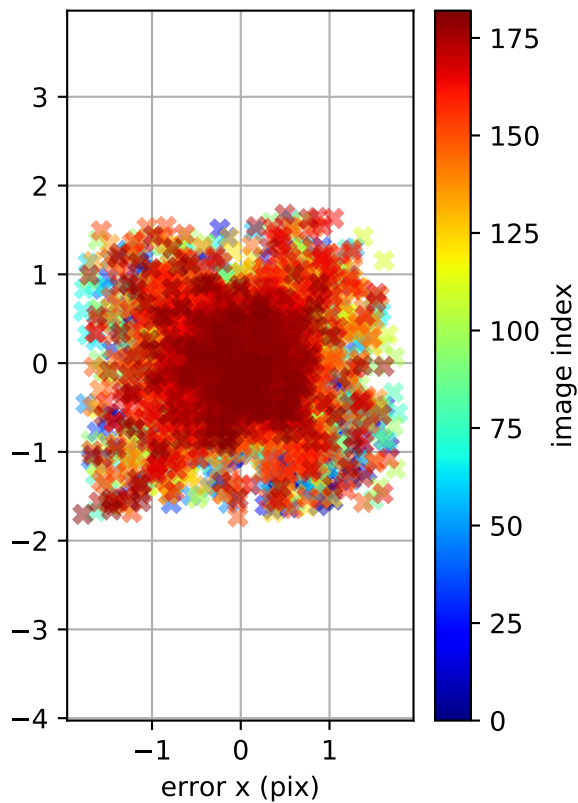
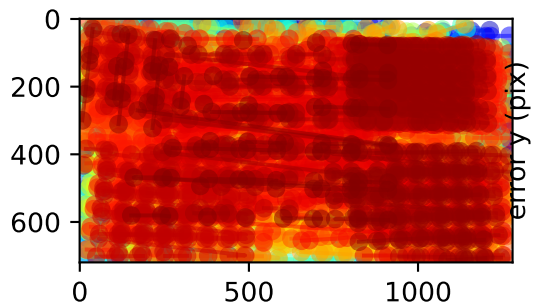
cam1: polar error



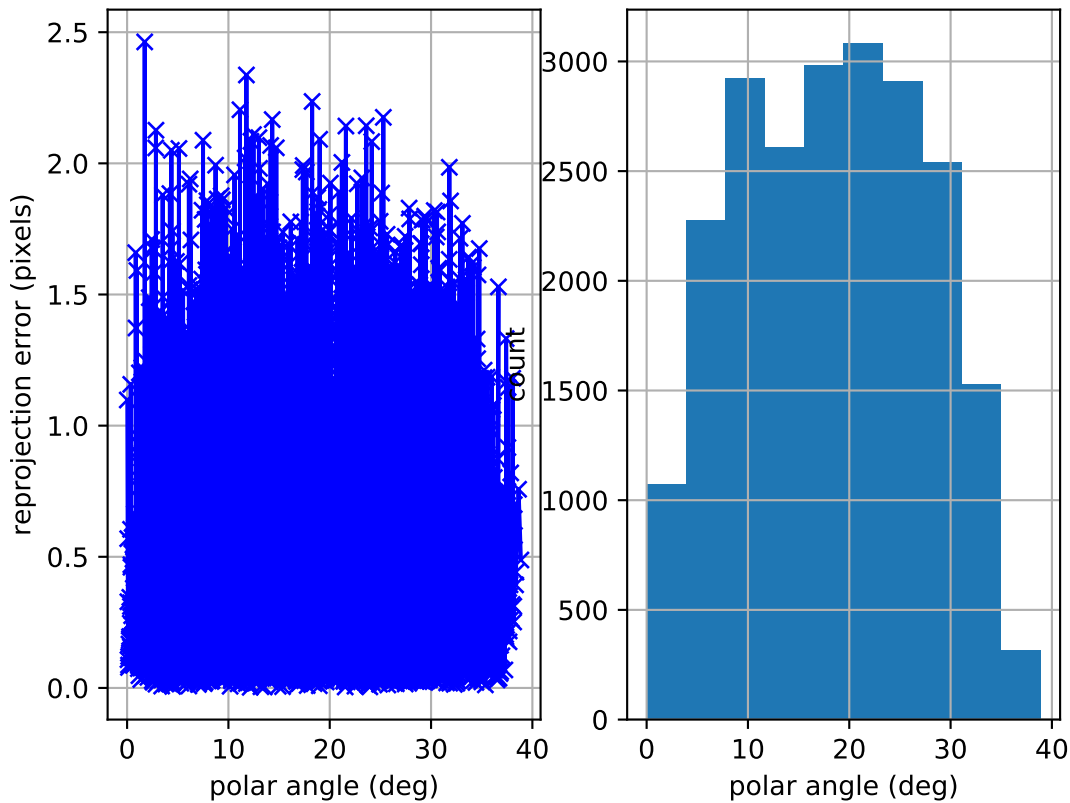
cam1: azimuthal error



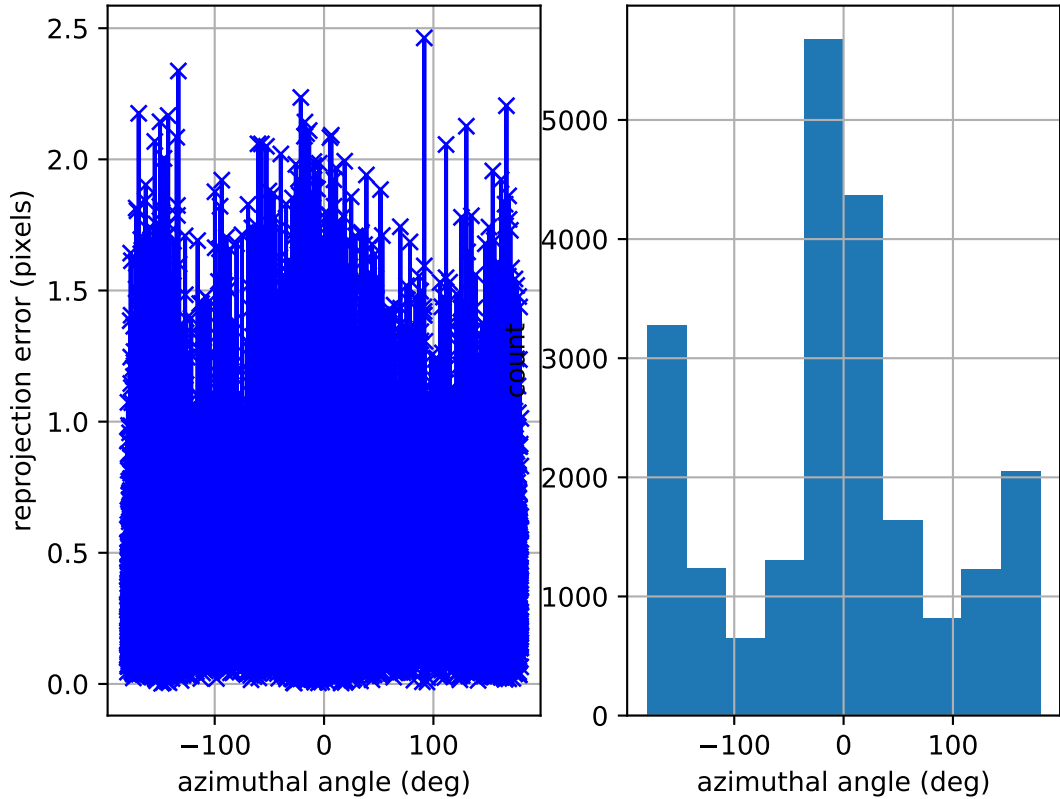
cam1: reprojection errors



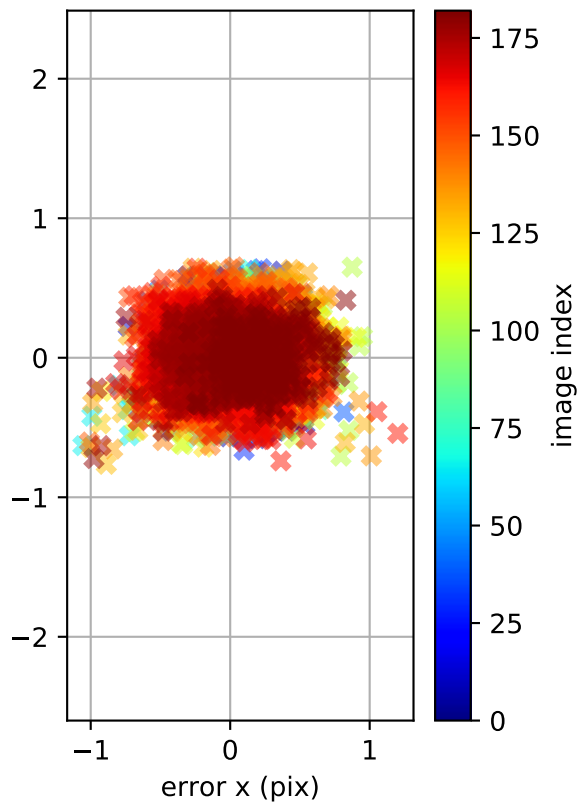
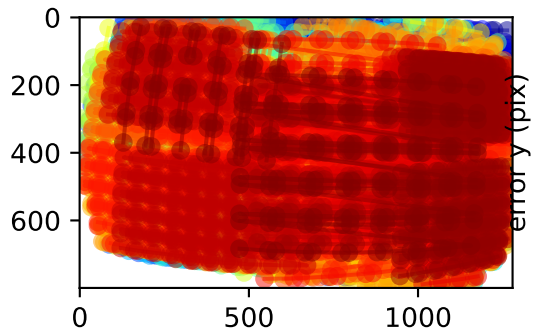
cam2: polar error



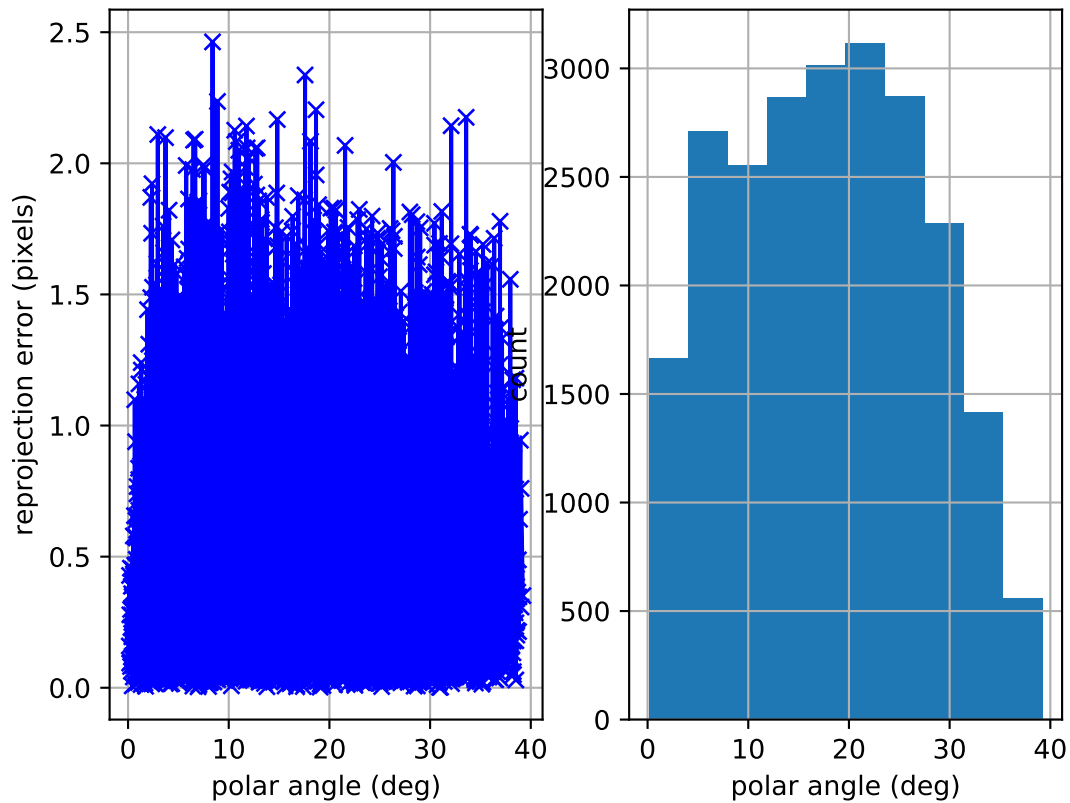
cam2: azimuthal error



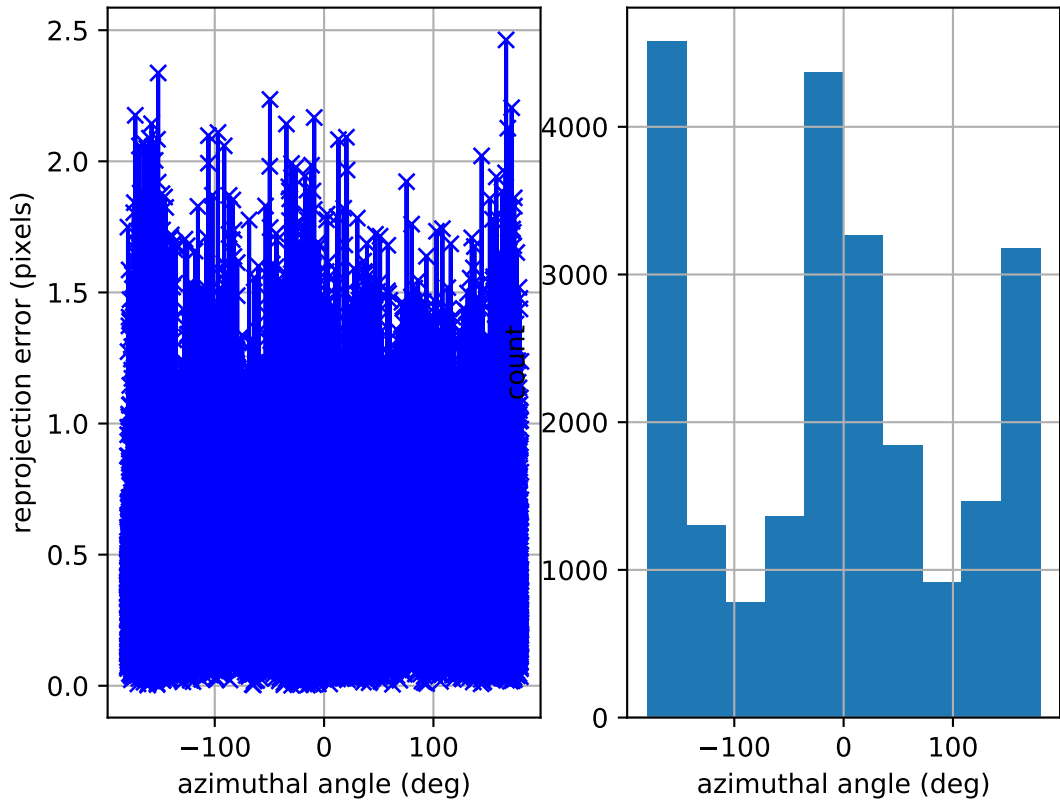
cam2: reprojection errors



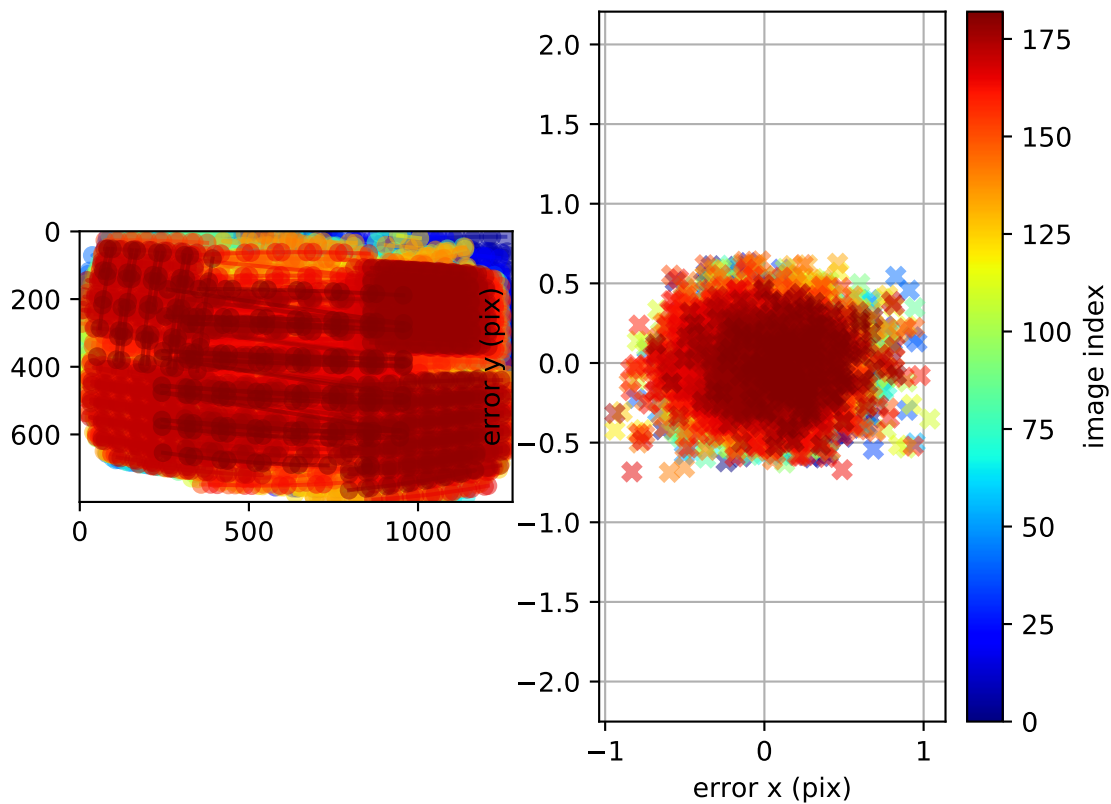
cam3: polar error



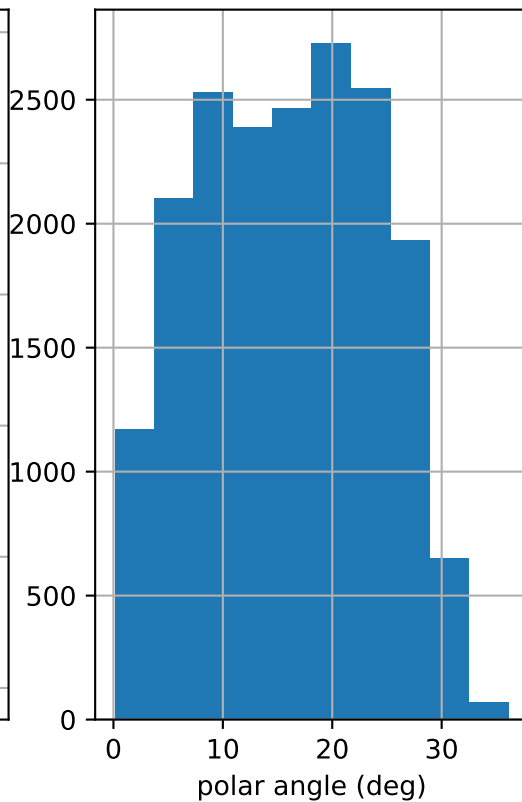
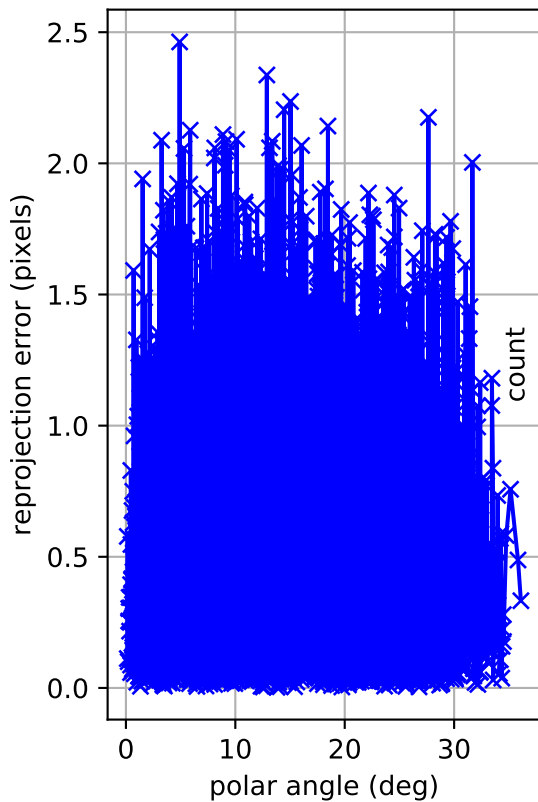
cam3: azimuthal error



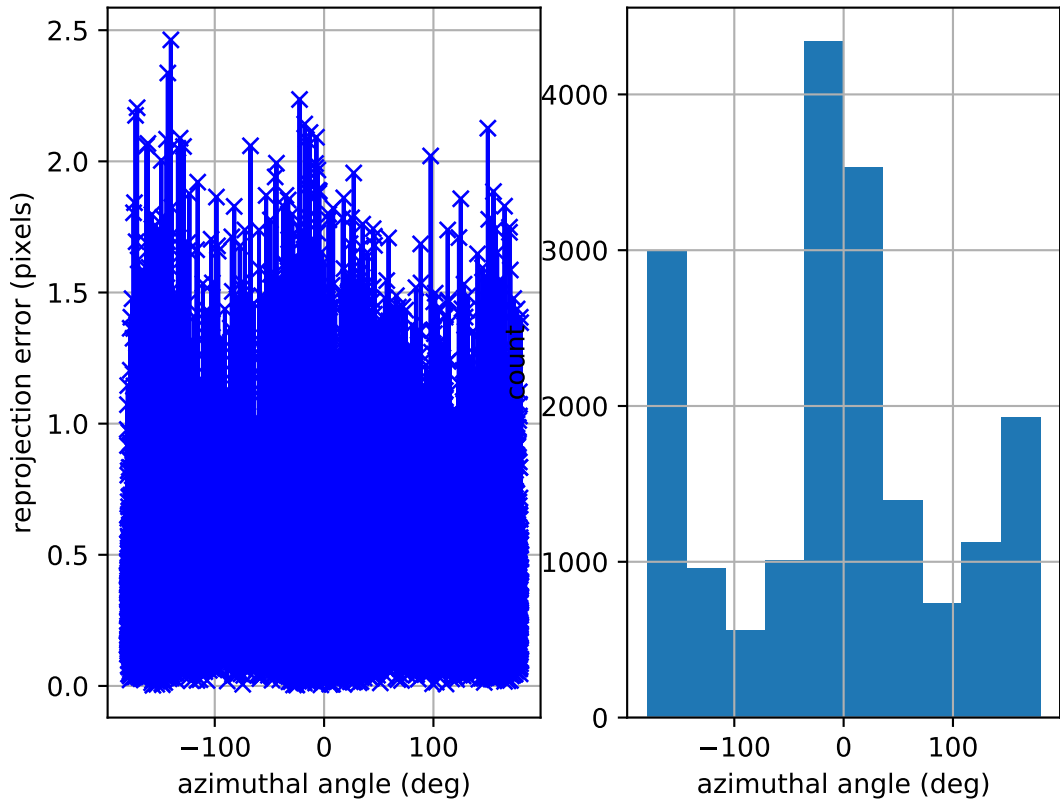
cam3: reprojection errors



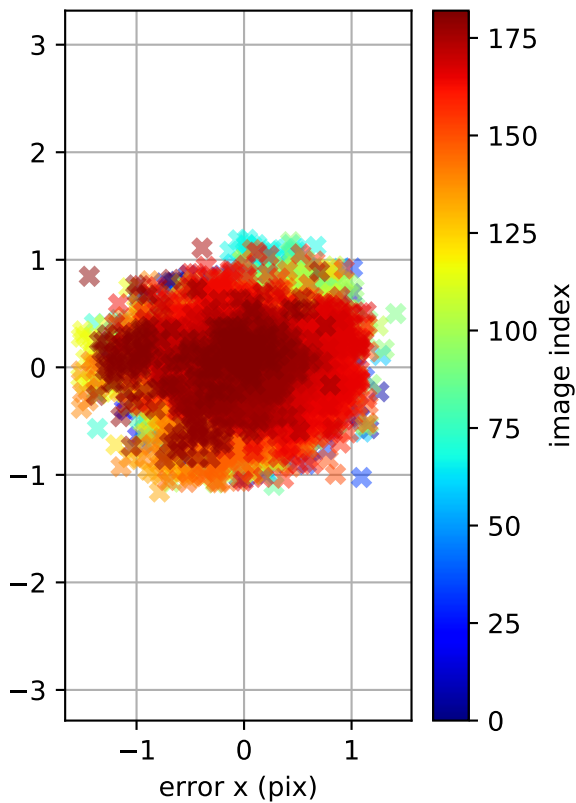
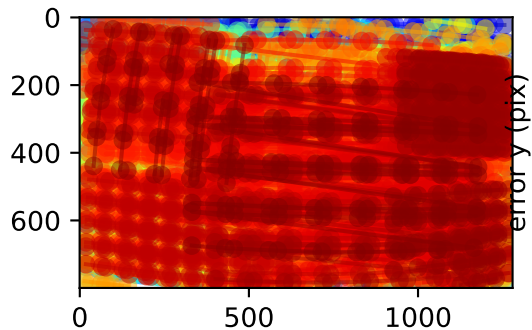
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

