

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04514347 0.07984973 0.00033703 -0.00161597] +- [0.0009832 0.00207979 0.00009828 0.0000569]
projection: [1031.52186613 1031.70276624 633.53886647 364.34446137] +- [0.15104485 0.15230326 0.02259652 0.22370309]

reprojection error: [0.000136, 0.000013] +- [0.337245, 0.312314]

cam1 (/prophesee/right/events):

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

distortion: [-0.05153314 0.08282881 0.00163985 -0.00060112] +- [0.0010288 0.00222793 0.00010358 0.00006153]
projection: [1030.29161359 1030.9024083 634.79835424 368.11576903] +- [0.09055575 0.08866487 0.01601995 0.23958439]

reprojection error: [0.000154, -0.000057] +- [0.424889, 0.397024]

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

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

distortion: [-0.39371687 0.15796959 -0.0001299 0.00058415] +- [0.00052578 0.00087005 0.00006016 0.00003647]
projection: [1058.53507719 1058.86556147 673.35721139 336.64714617] +- [0.19370344 0.19365263 0.03239658 0.21613039]

reprojection error: [0.000207, -0.000138] +- [0.166923, 0.143790]

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

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

distortion: [-0.39181332 0.15215209 -0.00033837 0.0011873] +- [0.00046566 0.00068836 0.00005873 0.00003923]
projection: [1052.38741575 1053.16775157 670.11431885 329.44162575] +- [0.20047245 0.20860372 0.05610127 0.21230207]

reprojection error: [0.000268, -0.000170] +- [0.179494, 0.144281]

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

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

distortion: [-0.41641827 0.18947145 0.00005384 0.0000641] +- [0.00074653 0.00177653 0.00006394 0.0000402]
projection: [1265.49880323 1265.55752907 651.88878969 367.95978292] +- [0.13000706 0.12824385 0.01775713 0.19640286]

reprojection error: [0.000083, 0.000002] +- [0.241325, 0.199361]

baseline T_1_0:

q: [-0.00150061 0.00182582 -0.00032112 0.99999716] +- [0.00034519 0.00005959 0.00003993]

t: [-0.12011332 0.00087946 -0.00028266] +- [0.00004375 0.00004504 0.00012284]

baseline T_2_1:

q: [-0.00039956 -0.00249898 -0.00507269 0.99998393] +- [0.0003358 0.00006202 0.00003732]

t: [0.12002017 0.06922868 0.0049721] +- [0.00004234 0.00004415 0.00015155]

baseline T_3_2:

q: [0.00016372 -0.00296171 0.00023573 0.99999557] +- [0.00029741 0.00010598 0.00003299]

t: [-0.11983816 -0.00011891 0.00060114] +- [0.00004163 0.00003886 0.0002195]

baseline T_4_3:

q: [0.00216484 0.00542261 0.0004781 0.99998284] +- [0.00028608 0.00009109 0.00003284]

t: [0.08857586 0.00620944 0.00407802] +- [0.00003996 0.00003568 0.00017969]

Target configuration

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Type: aprilgrid

Tags:

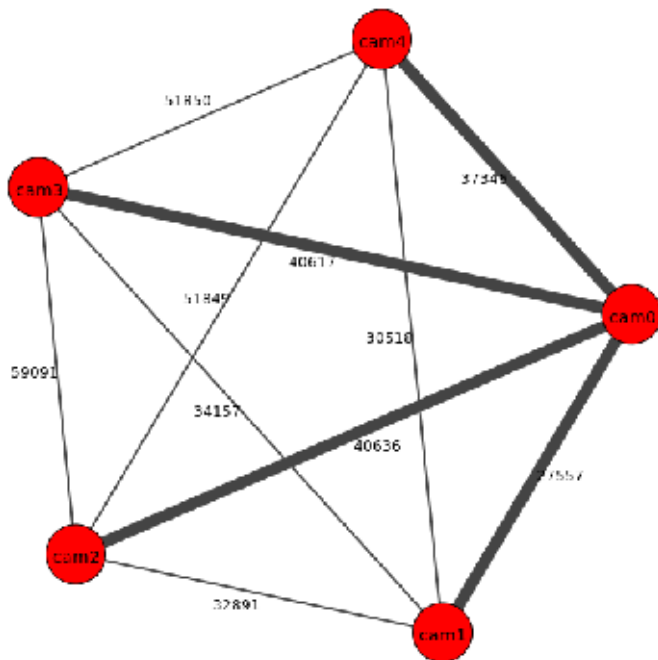
Rows: 5

Cols: 7

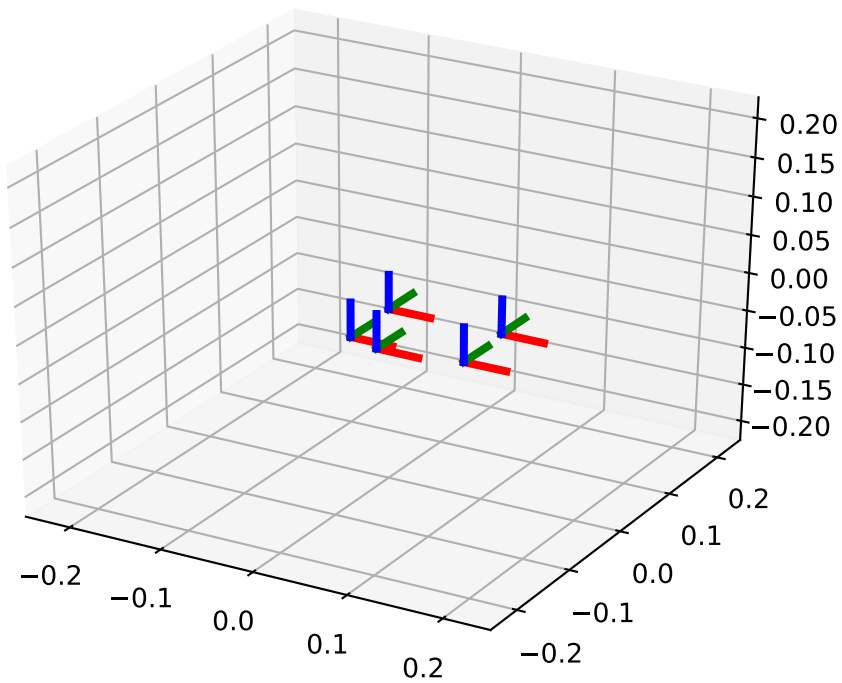
Size: 0.04 [m]

Spacing 0.01 [m]

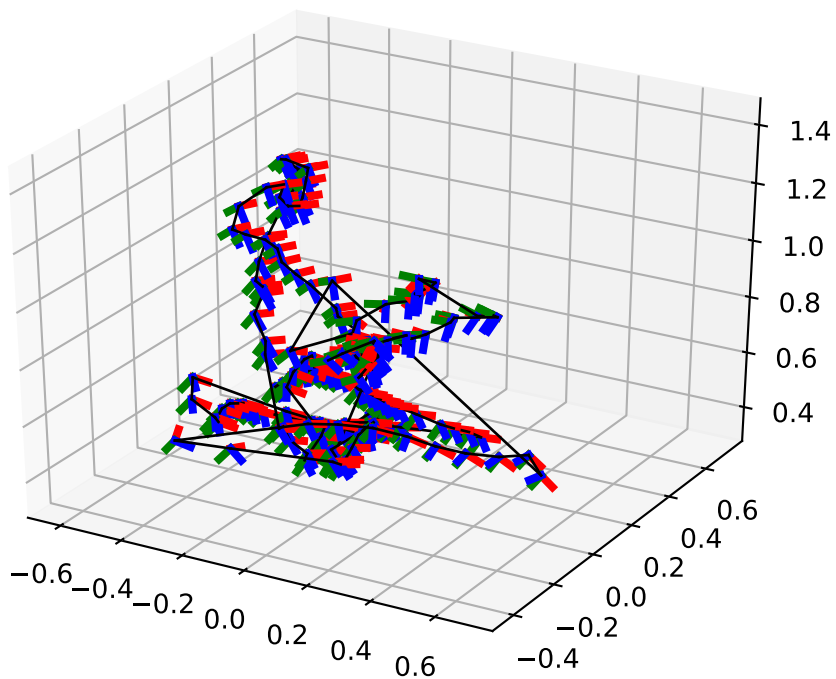
Inter-camera observations graph (edge weight=#mutual obs.)



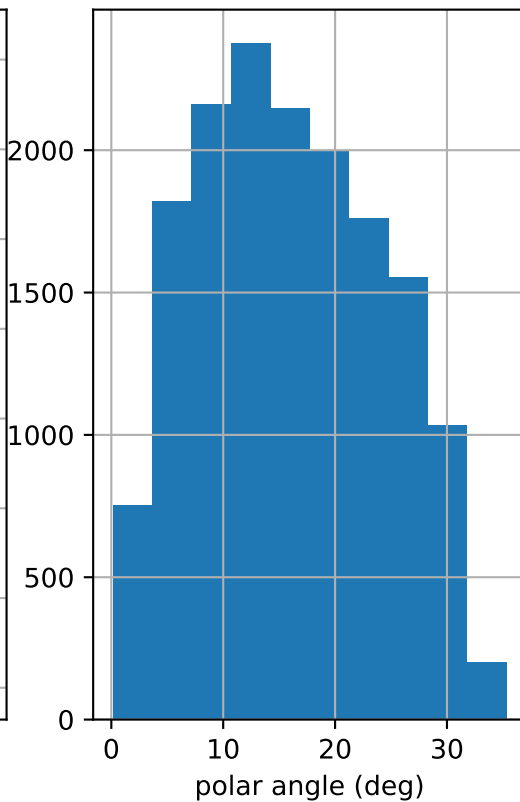
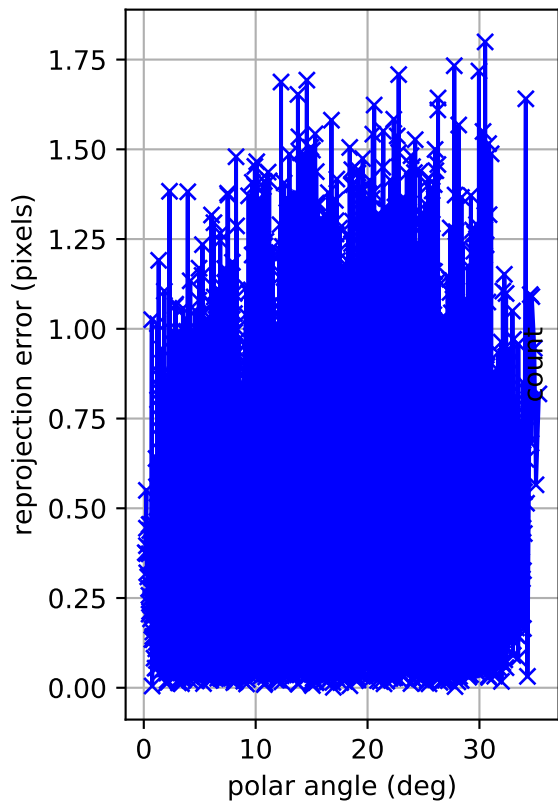
camera system



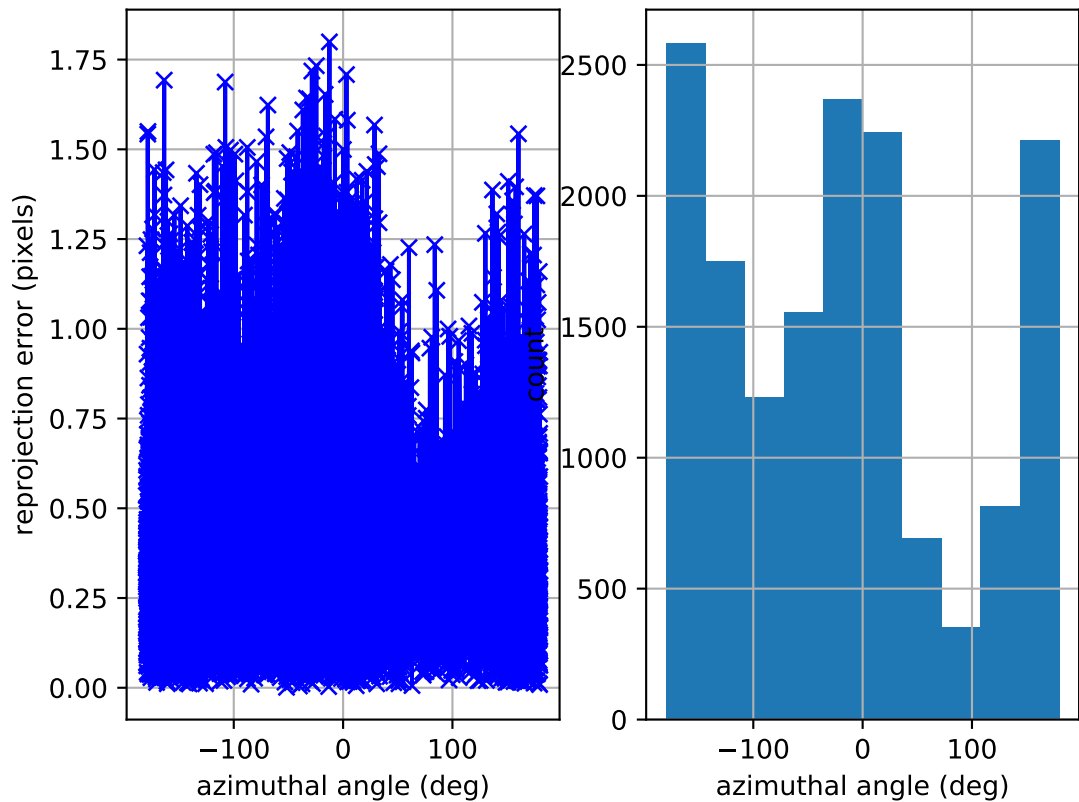
cam0: estimated poses



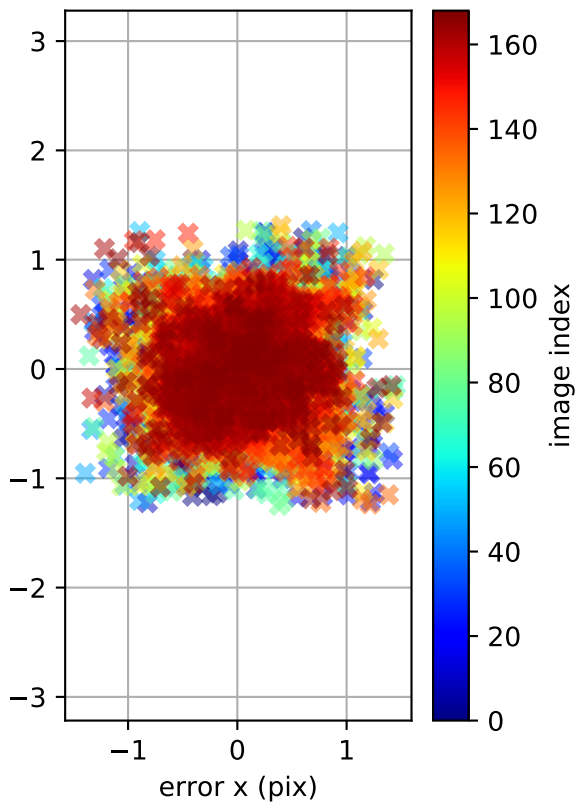
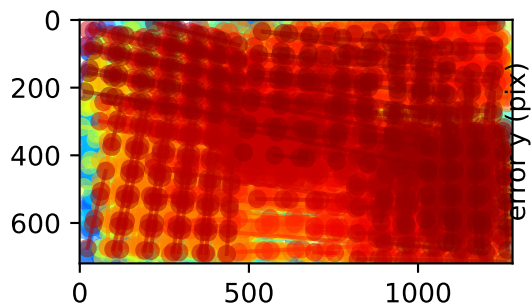
cam0: polar error



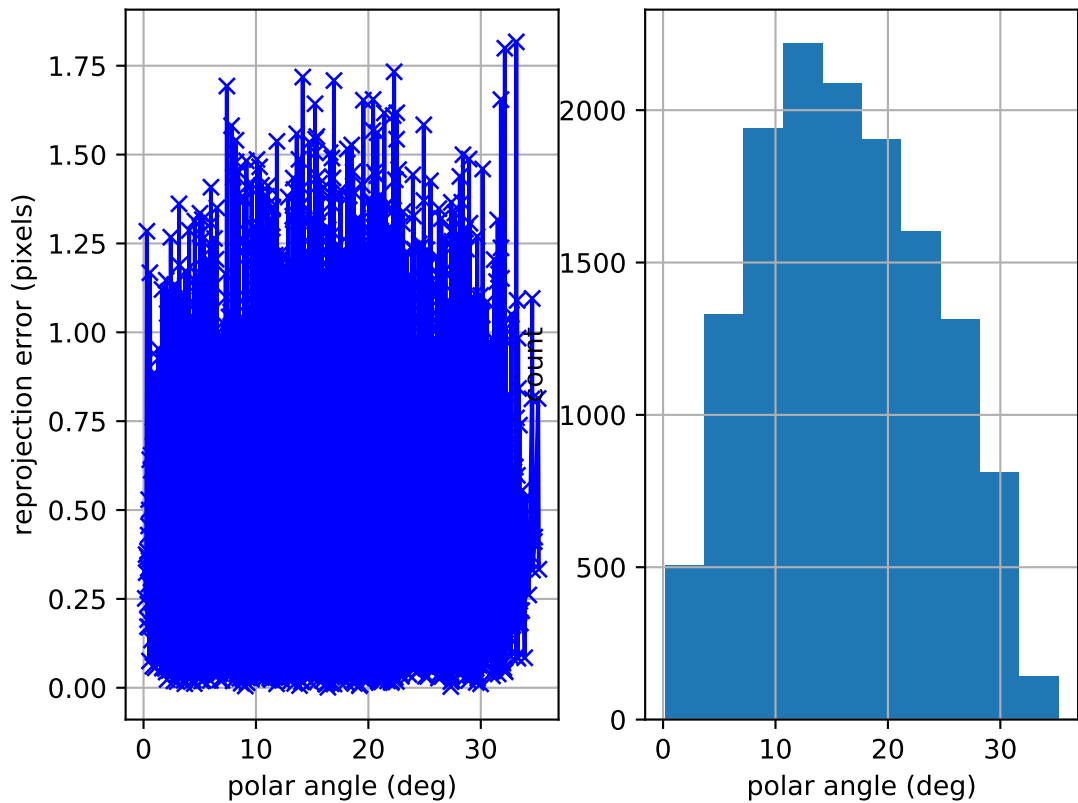
cam0: azimuthal error



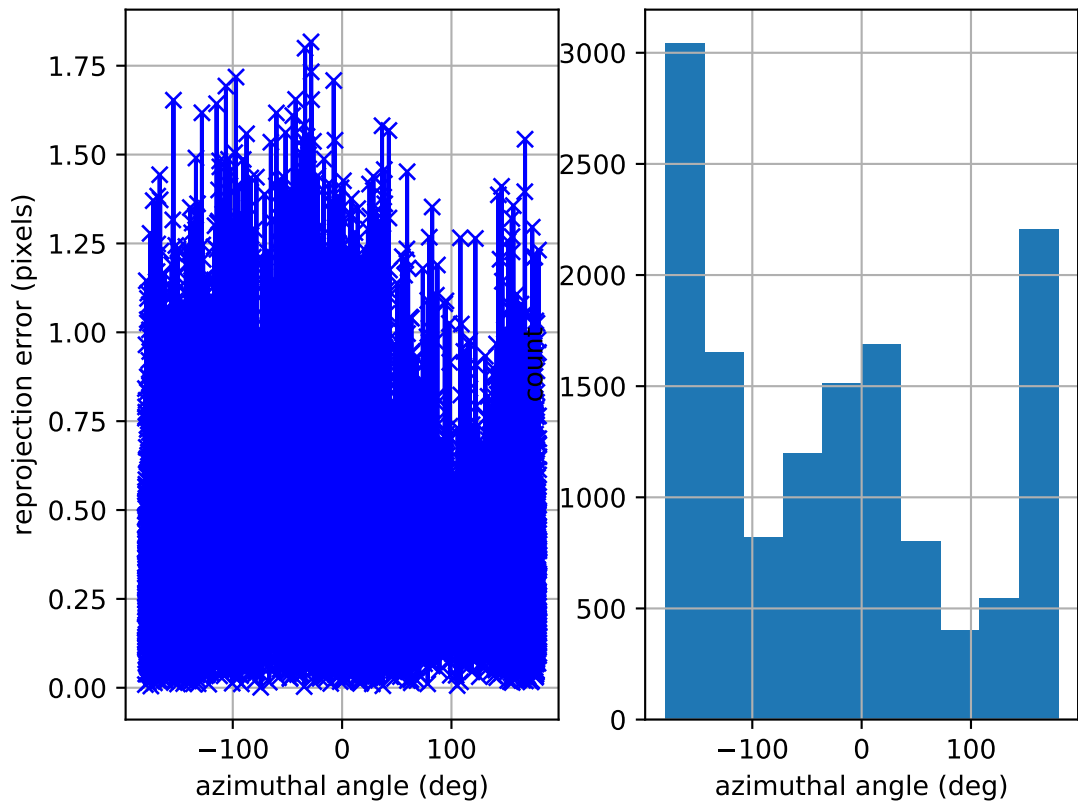
cam0: reprojection errors



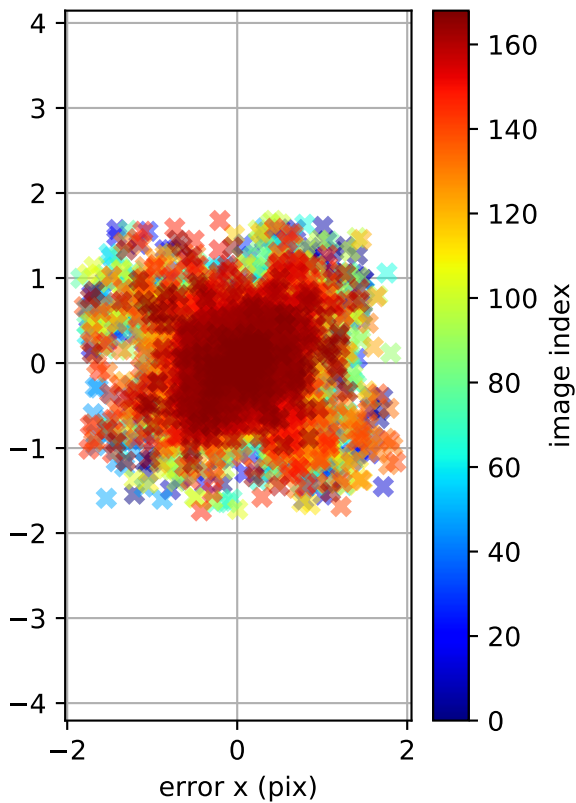
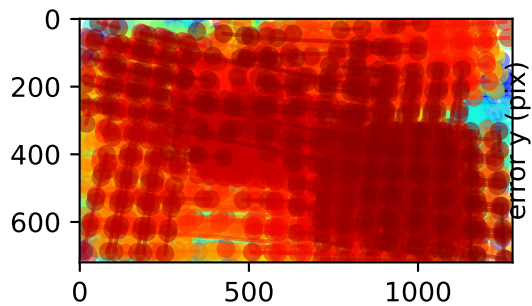
cam1: polar error



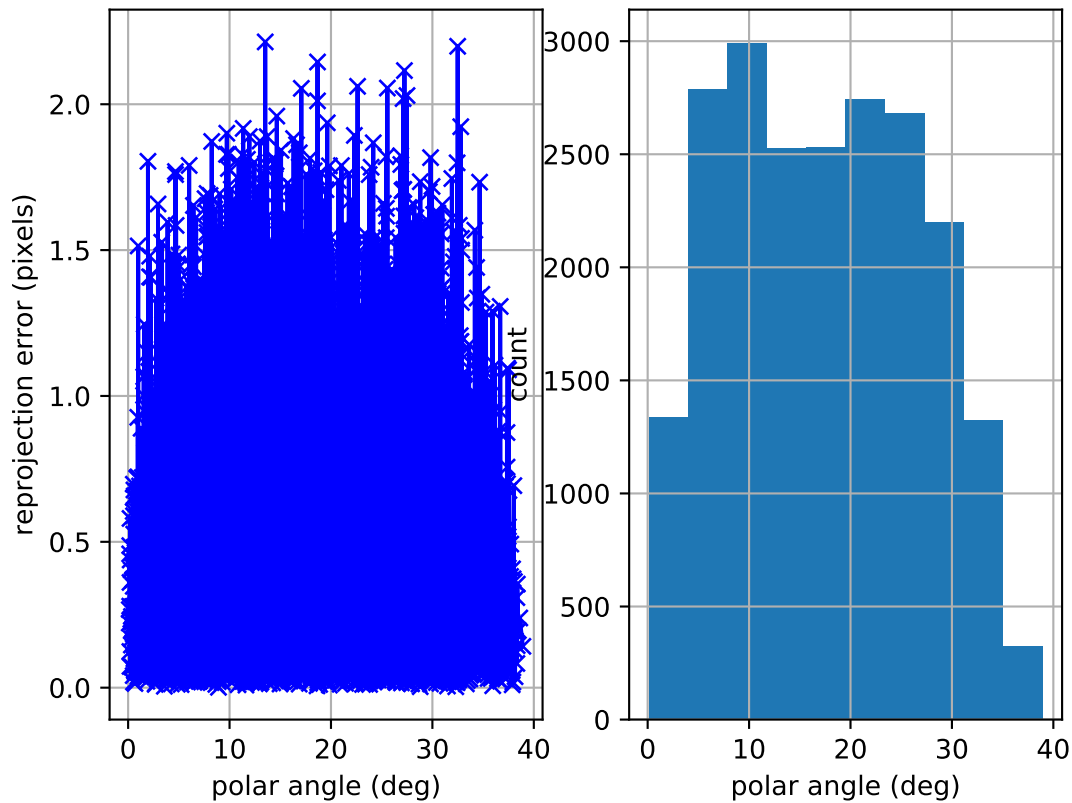
cam1: azimuthal error



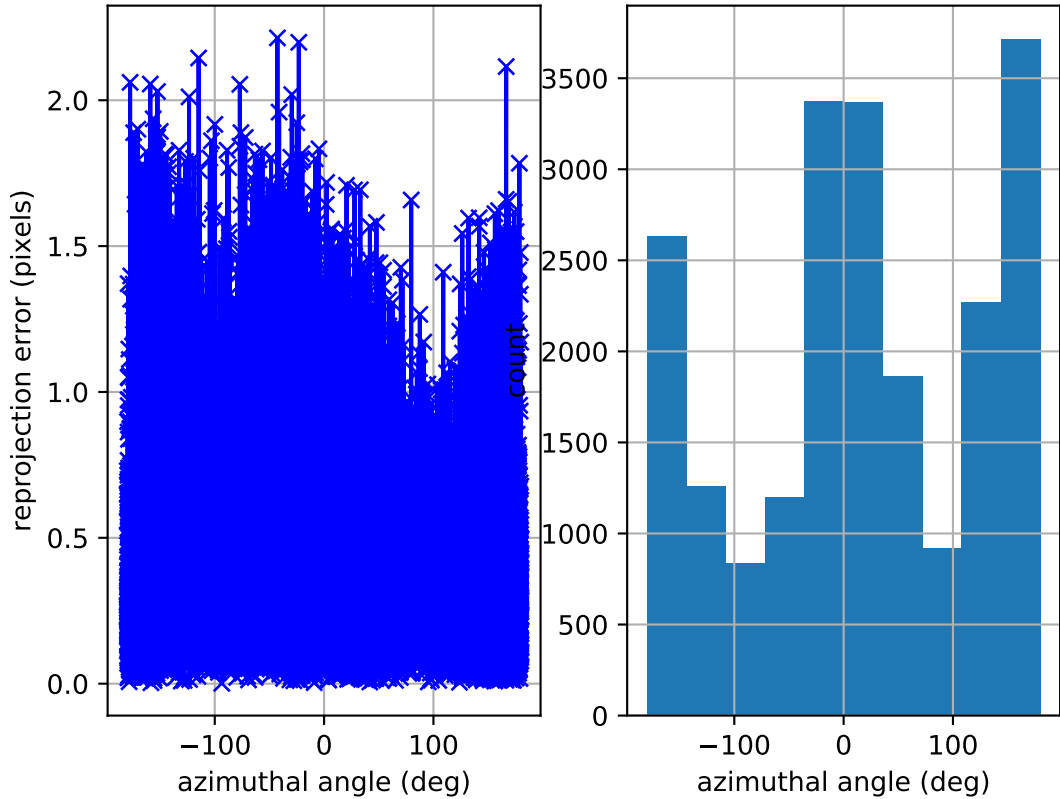
cam1: reprojection errors



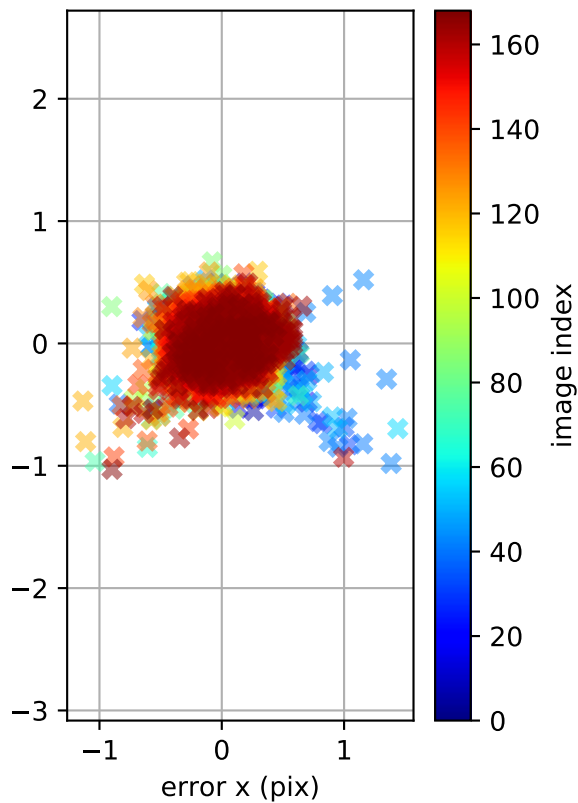
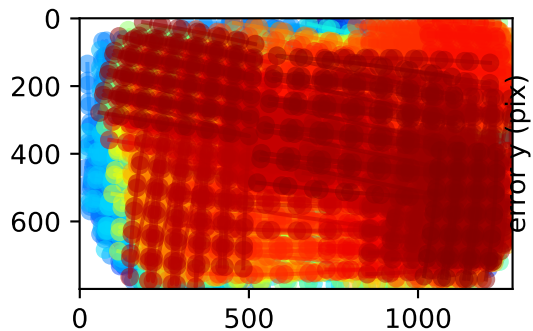
cam2: polar error



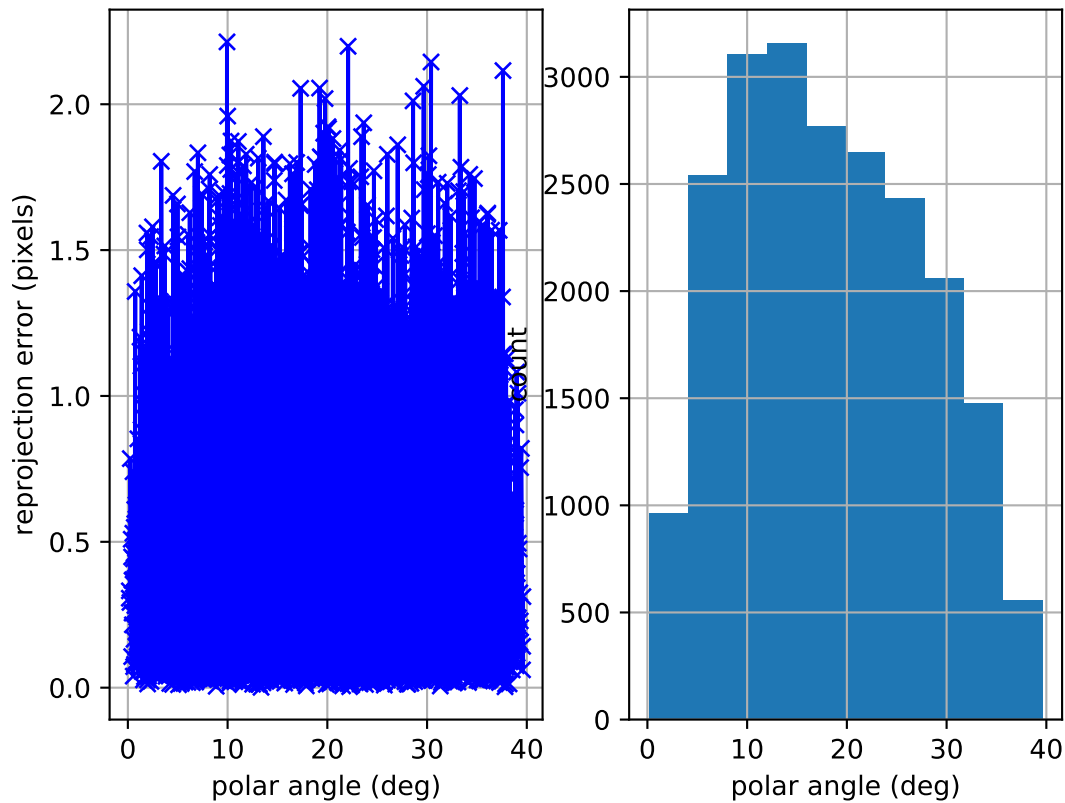
cam2: azimuthal error



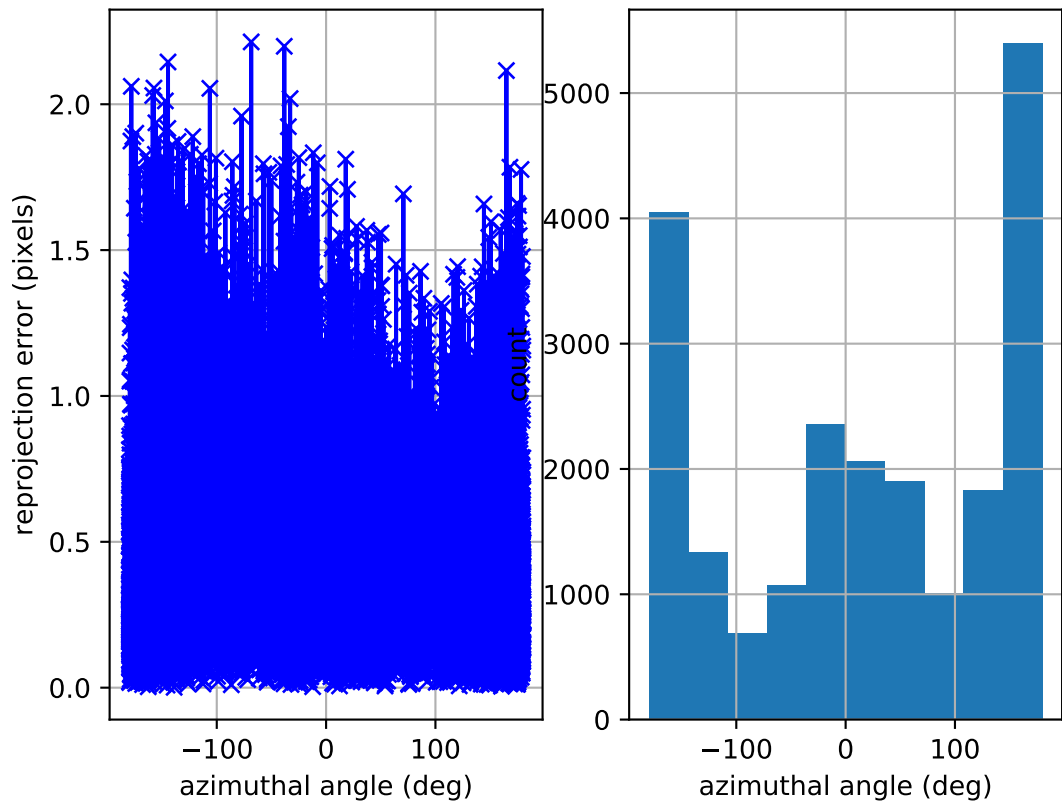
cam2: reprojection errors



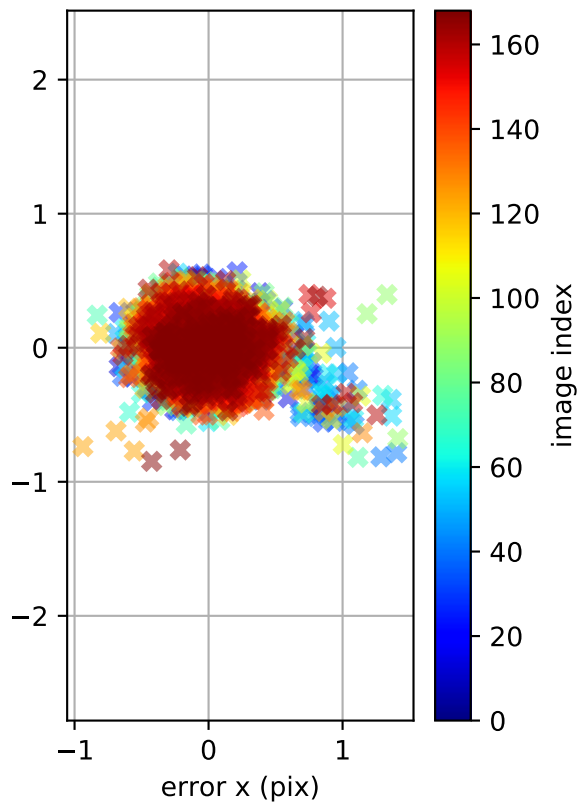
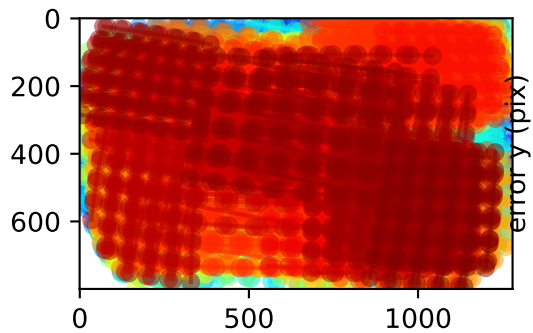
cam3: polar error



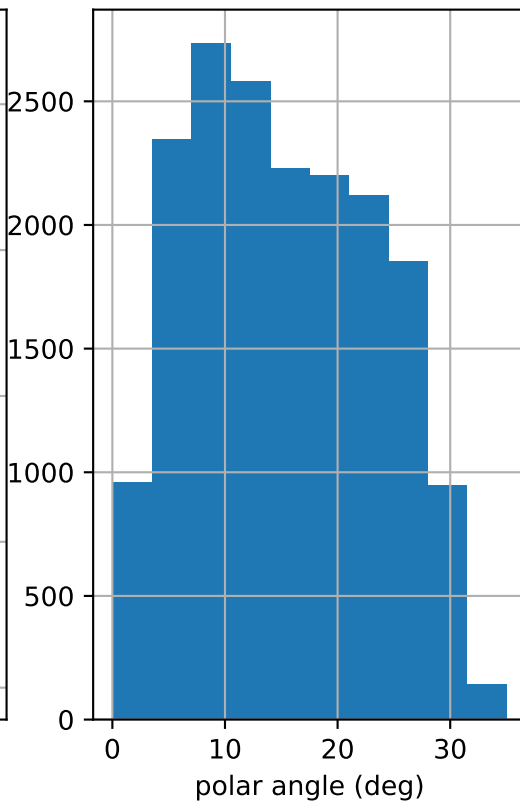
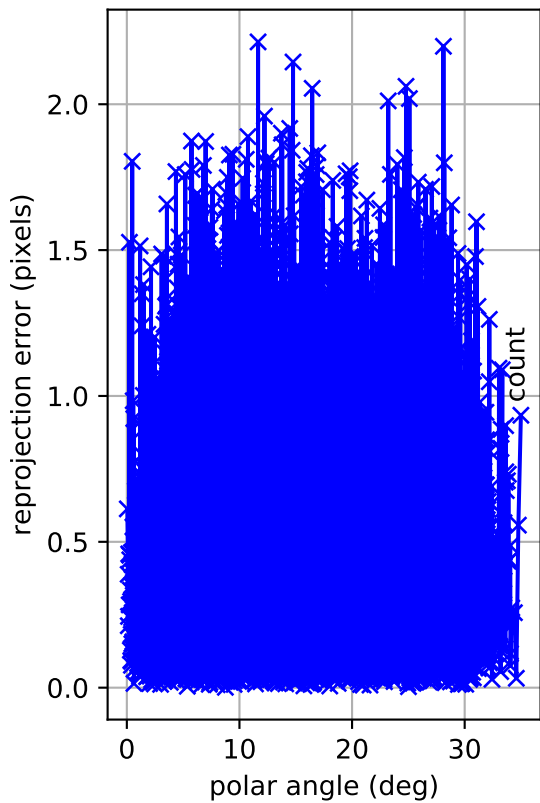
cam3: azimuthal error



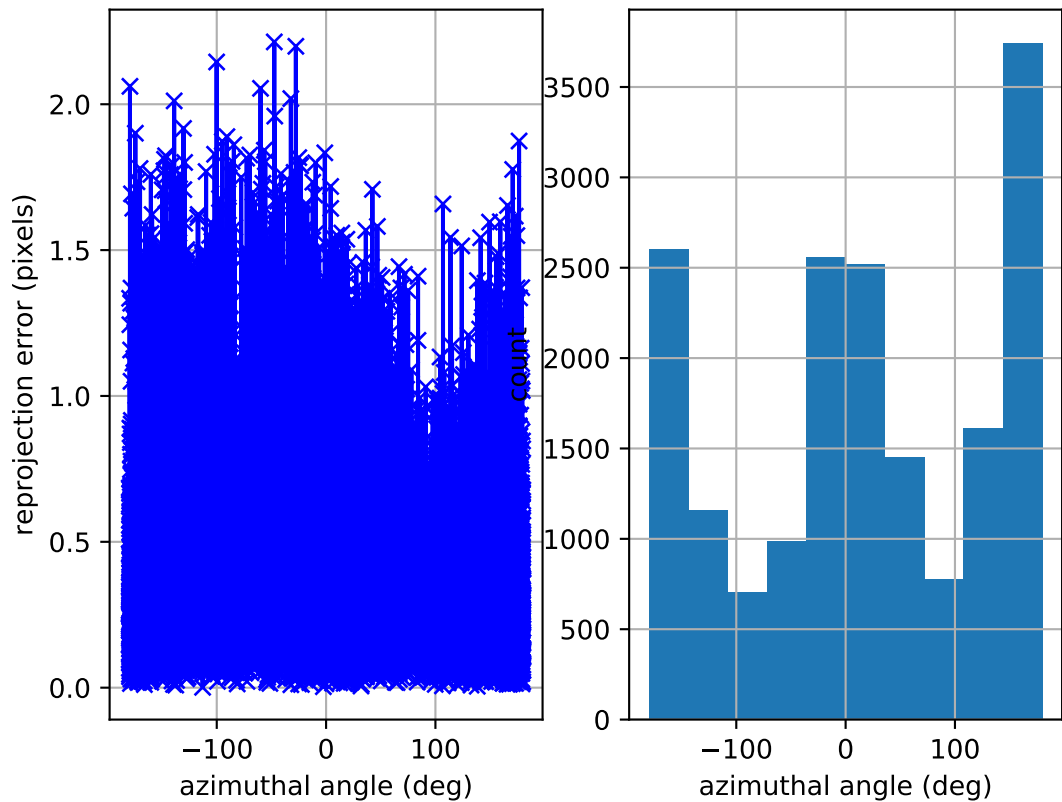
cam3: reprojection errors



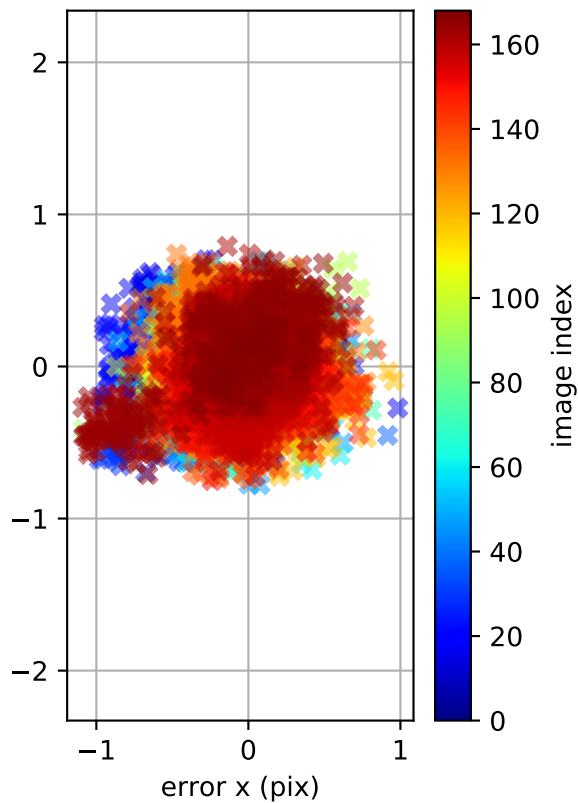
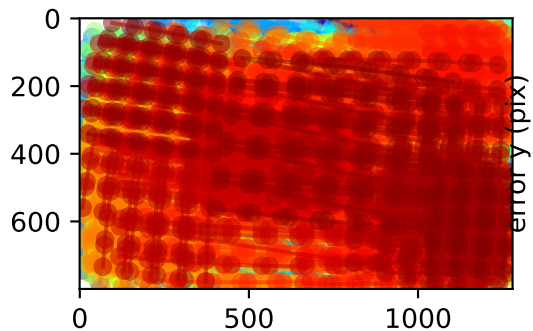
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

