

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04615764 0.0816728 0.00000179 -0.0006529] +- [0.00095342 0.00205819 0.00008482 0.00005282]
projection: [1033.96932043 1033.73045672 635.41880733 365.06039341] +- [0.13258981 0.13309646 0.00640439
0.20545518]

reprojection error: [0.000354, 0.000108] +- [0.828292, 0.530086]

cam1 (/prophesee/right/events):

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

distortion: [-0.04754005 0.07643938 0.00208795 0.0000453] +- [0.00096664 0.00206386 0.00008266 0.00005783]
projection: [1033.11454613 1033.14296044 635.98612158 371.3118031] +- [0.13643368 0.13734269 0.01087903
0.18031403]

reprojection error: [0.000472, -0.000227] +- [0.801116, 0.549454]

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

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

distortion: [-0.39437529 0.15777161 -0.00046252 0.00058845] +- [0.00048062 0.00078044 0.00004803 0.00003219]
projection: [1059.82157154 1060.14063952 673.26994811 340.48532827] +- [0.11475035 0.11619533 0.01569681
0.18462007]

reprojection error: [0.000499, -0.000431] +- [0.408745, 0.266178]

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

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

distortion: [-0.39115607 0.14874087 -0.00053701 0.00120265] +- [0.00039384 0.00054779 0.00004756 0.00003568]
projection: [1054.79301247 1055.50303513 672.34852361 330.91662823] +- [0.11281184 0.11566369 0.00818871
0.17677697]

reprojection error: [0.000337, -0.000017] +- [0.417482, 0.266831]

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

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

distortion: [-0.41740286 0.19015788 -0.0003519 0.00008768] +- [0.00077719 0.00184281 0.00005189 0.00003854]
projection: [1267.97577438 1268.04863081 653.55571875 373.38181194] +- [0.13516888 0.13258547 0.00414332
0.06231353]

reprojection error: [-0.000062, -0.000349] +- [0.557144, 0.407138]

baseline T_1_0:

q: [-0.00277476 0.00162257 -0.00041532 0.99999475] +- [0.00033155 0.00005321 0.00003674]

t: [-0.12007655 0.00087446 0.00004232] +- [0.000032 0.00003047 0.00010085]

baseline T_2_1:

q: [-0.00047297 -0.00371802 -0.00502258 0.99998036] +- [0.00029925 0.00005387 0.00003426]

t: [0.12001191 0.06896064 0.00452625] +- [0.00003013 0.00002908 0.00009589]

baseline T_3_2:

q: [0.0012901 -0.00104728 0.00015891 0.99999861] +- [0.00026019 0.00004817 0.00002915]

t: [-0.12006061 -0.00012405 0.00095287] +- [0.00002729 0.00002609 0.00008602]

baseline T_4_3:

q: [0.00061744 0.00455263 0.00042614 0.99998936] +- [0.00020072 0.00004206 0.00003017]

t: [0.088899 0.00619342 0.00349201] +- [0.00002649 0.00002524 0.00009043]

Target configuration

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Type: aprilgrid

Tags:

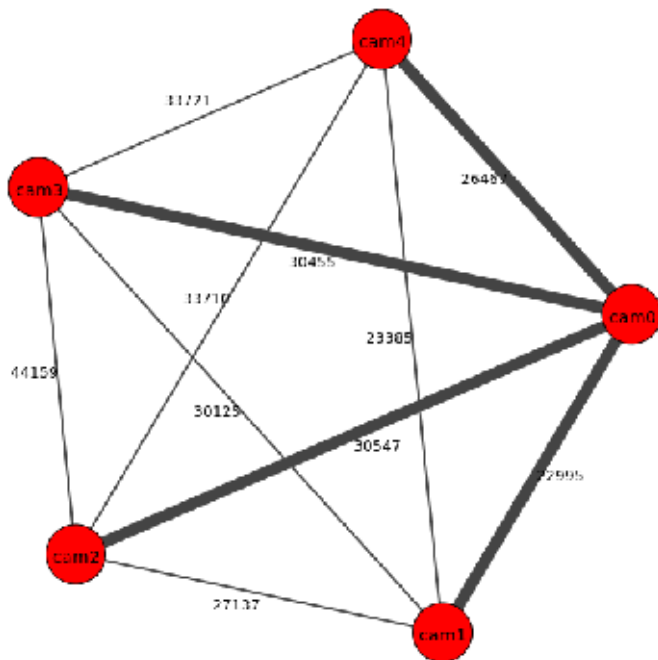
Rows: 5

Cols: 7

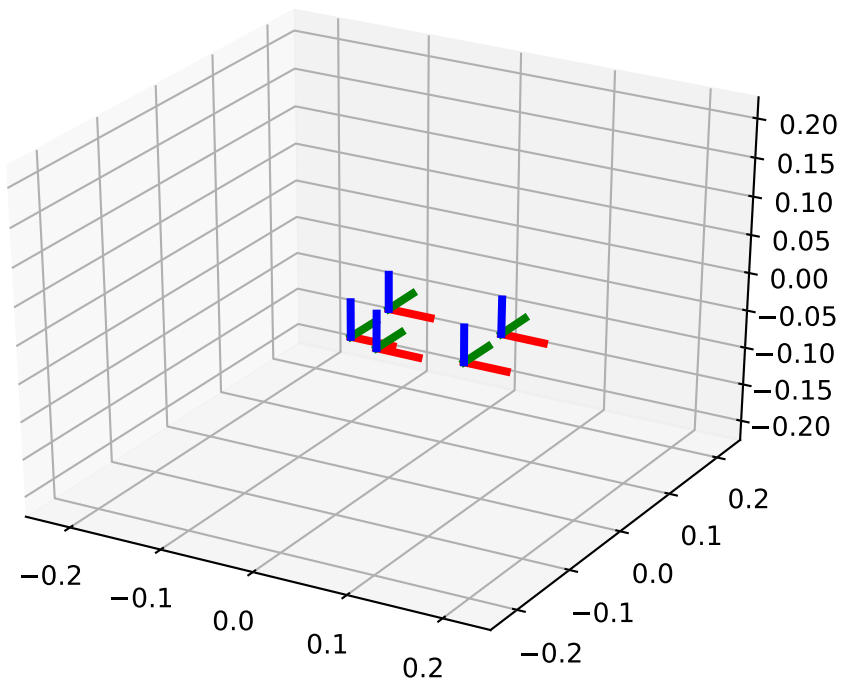
Size: 0.04 [m]

Spacing 0.01 [m]

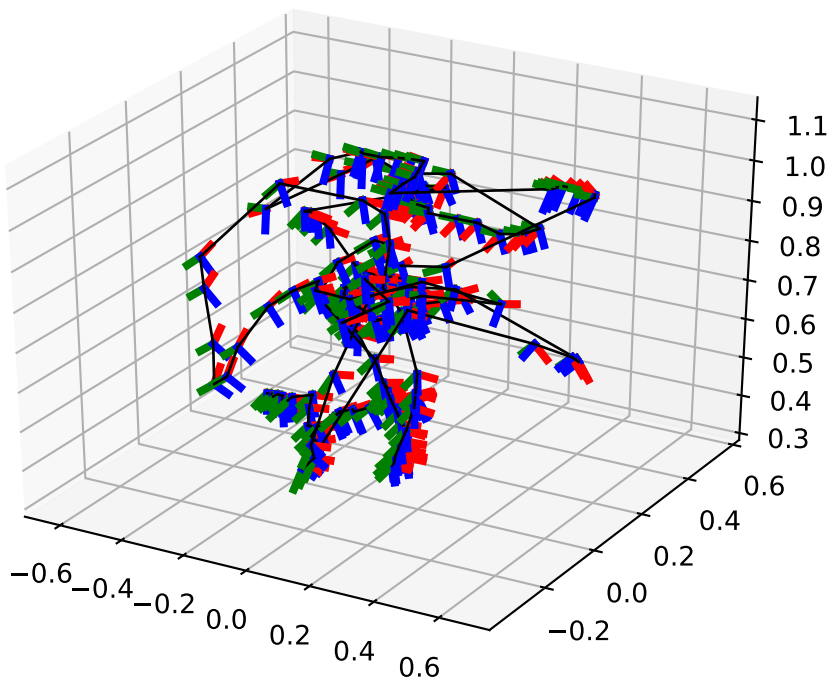
Inter-camera observations graph (edge weight=#mutual obs.)



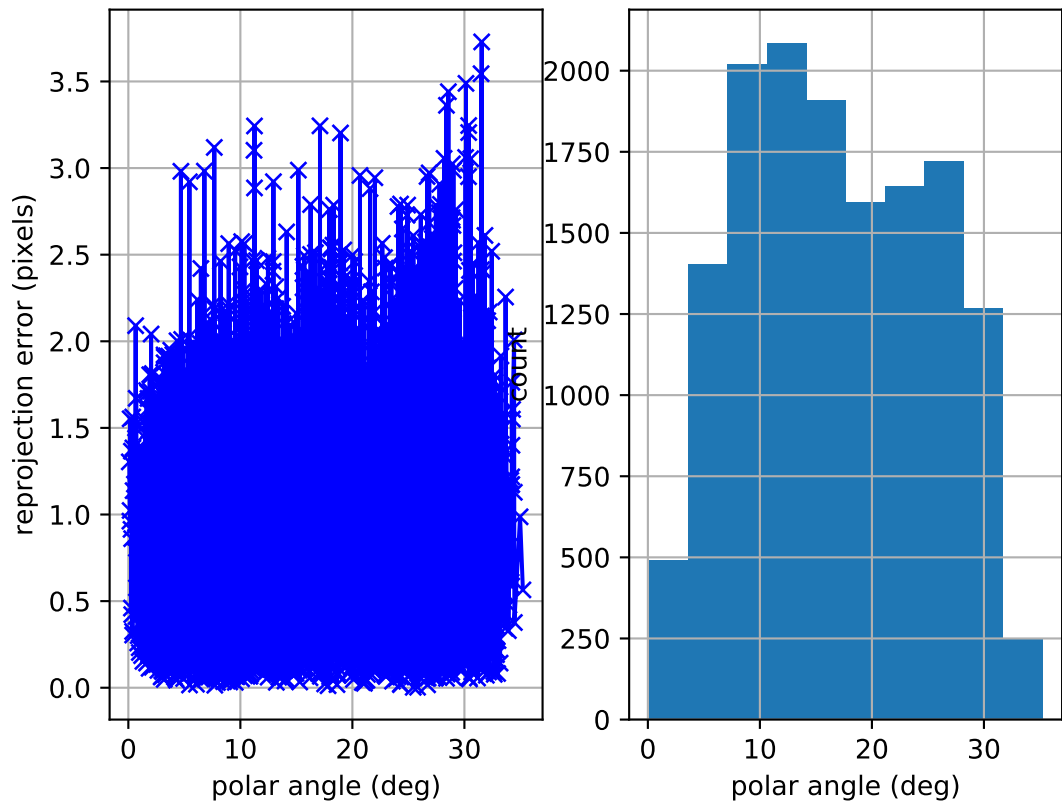
camera system



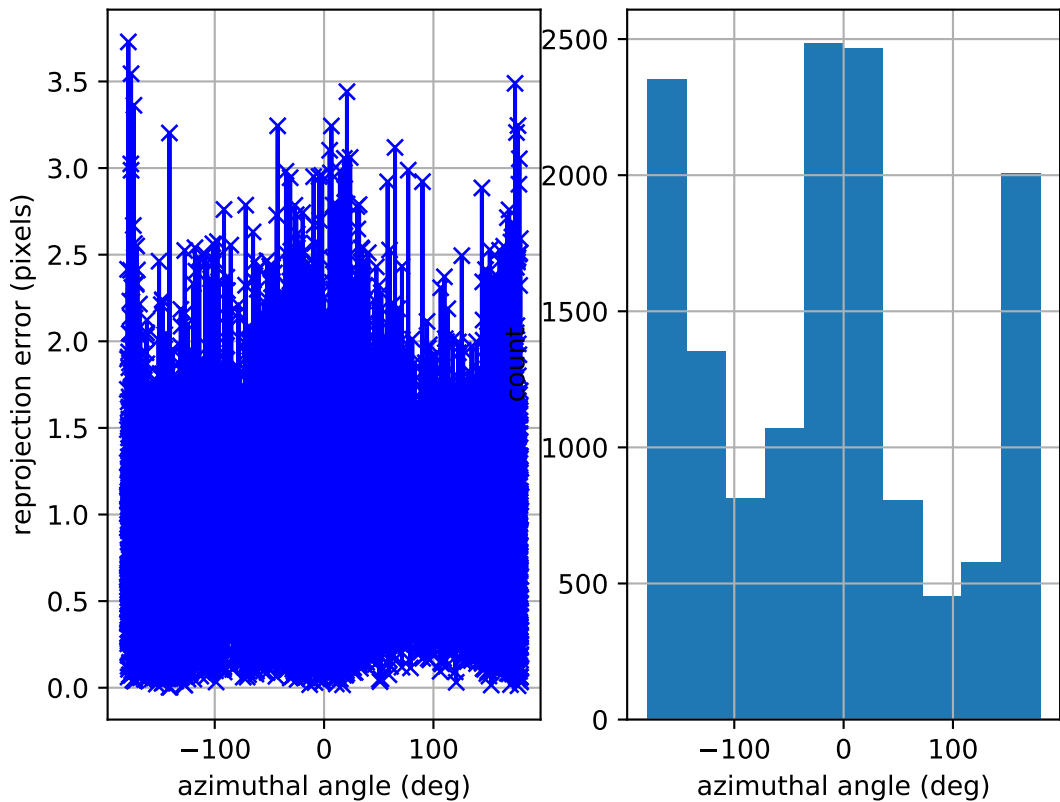
cam0: estimated poses



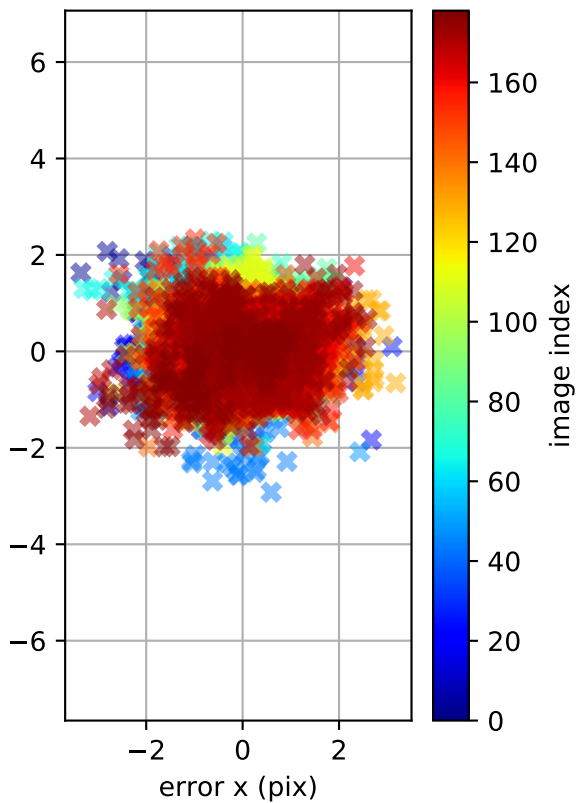
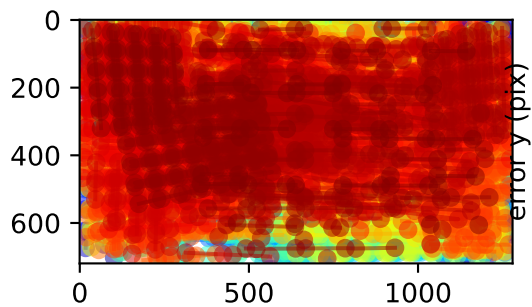
cam0: polar error



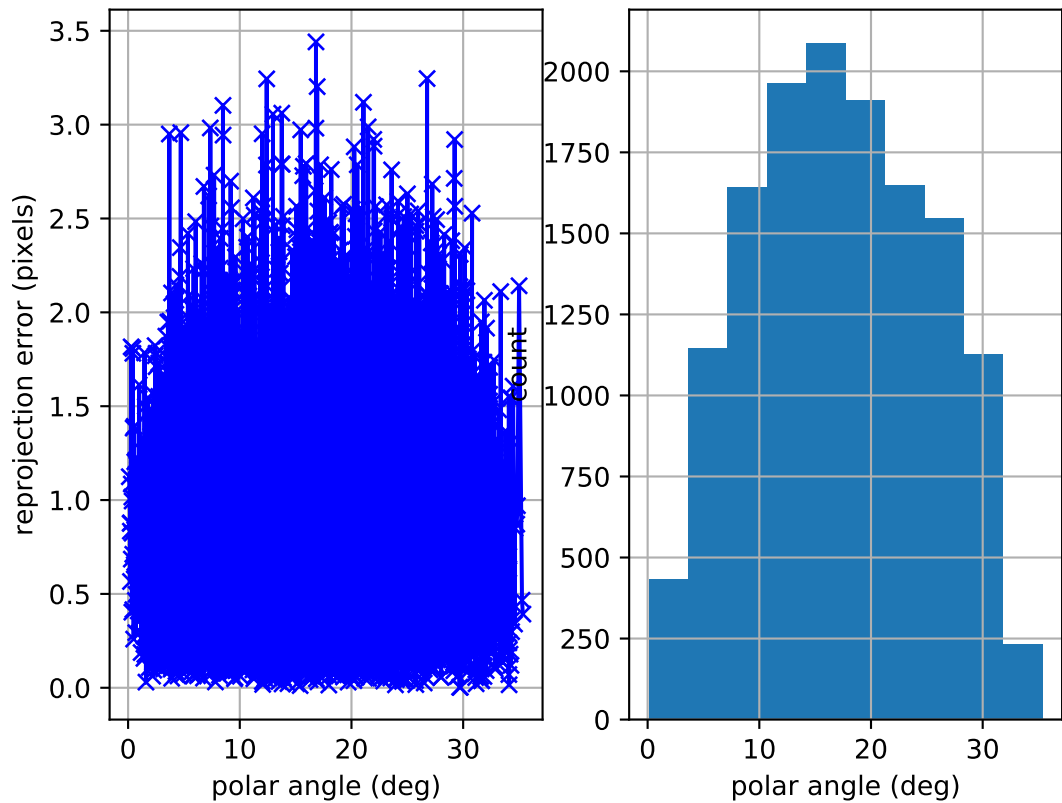
cam0: azimuthal error



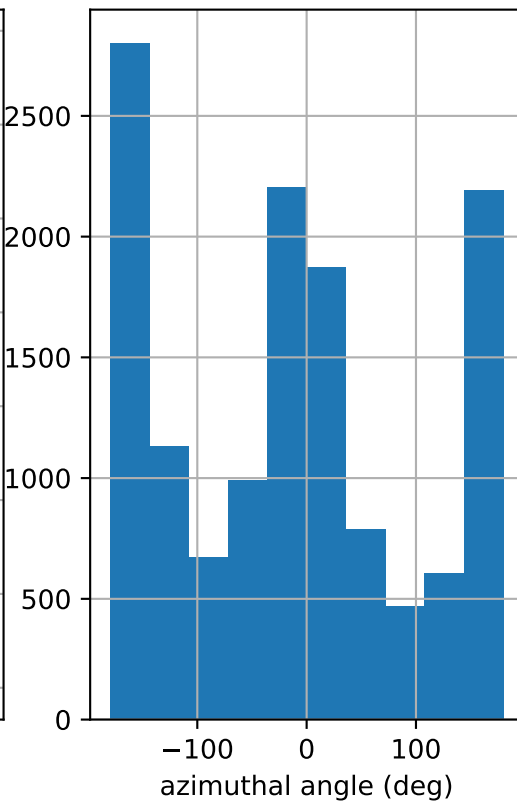
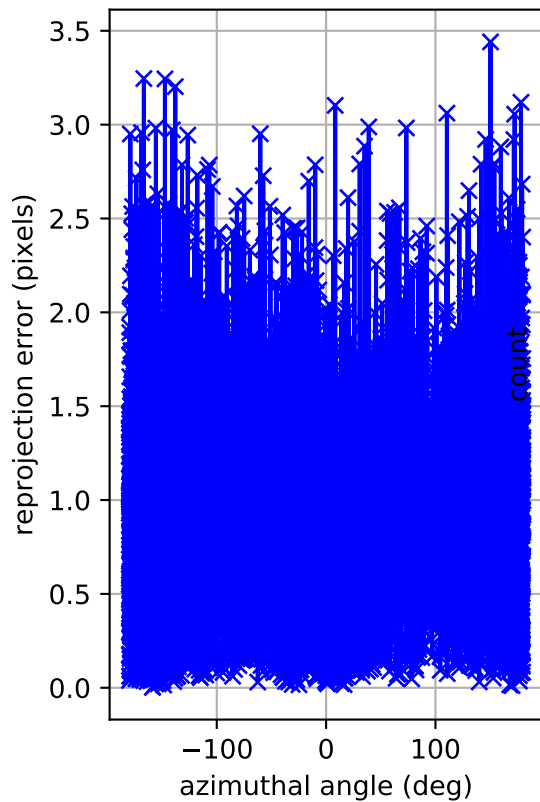
cam0: reprojection errors



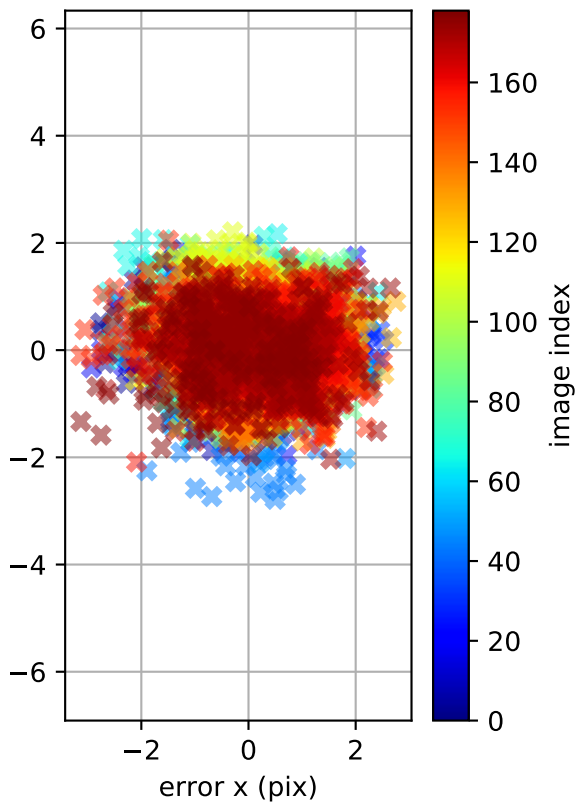
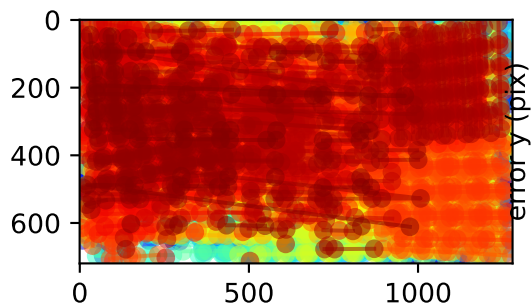
cam1: polar error



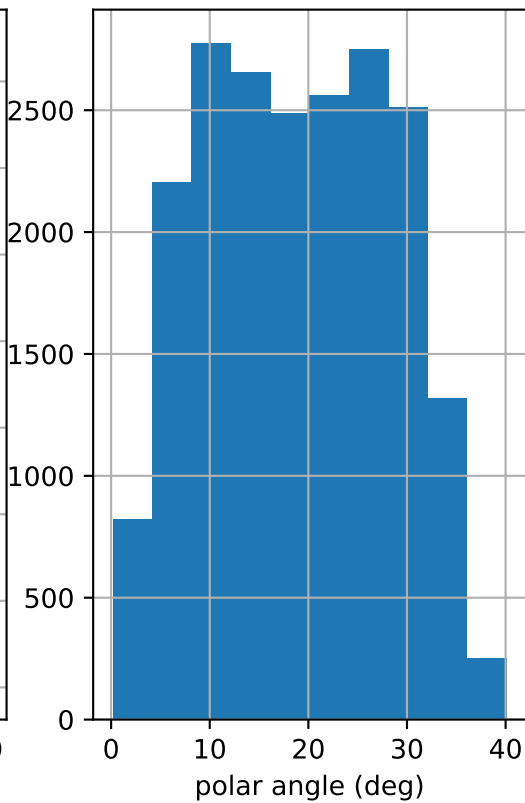
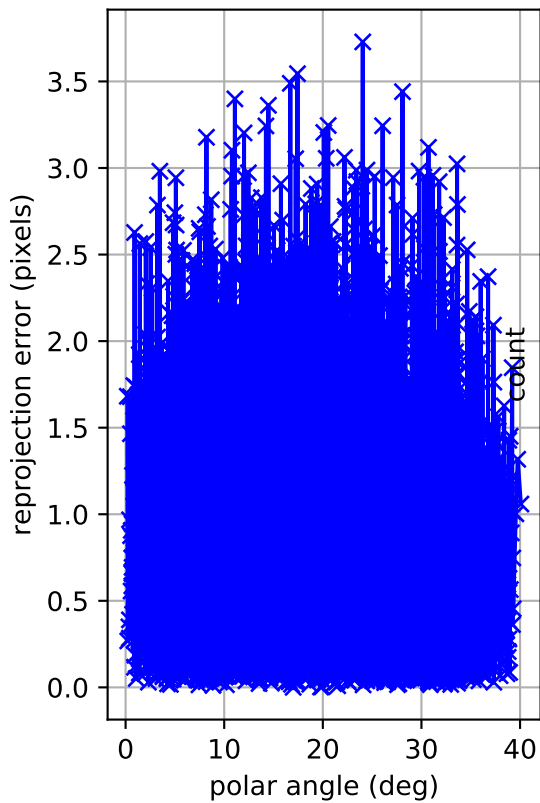
cam1: azimuthal error



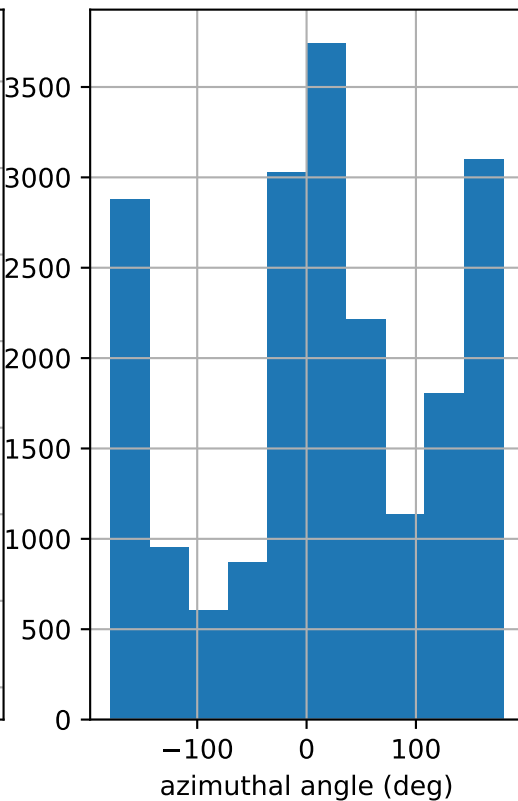
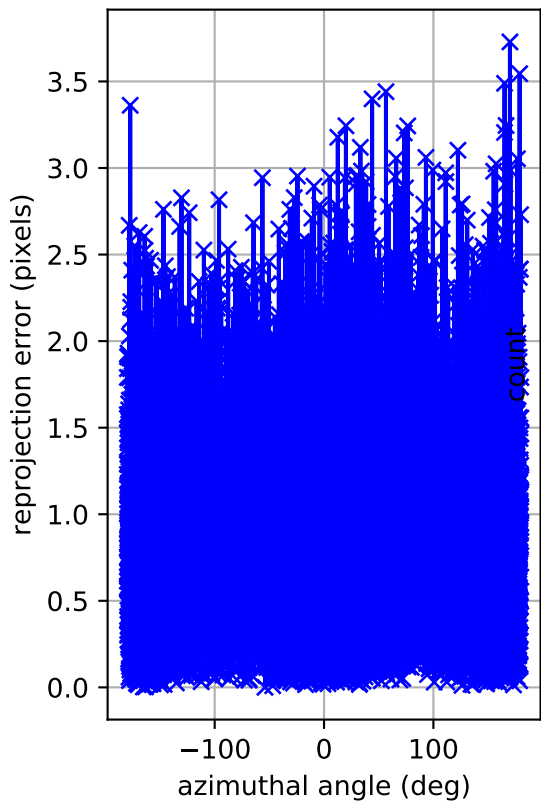
cam1: reprojection errors



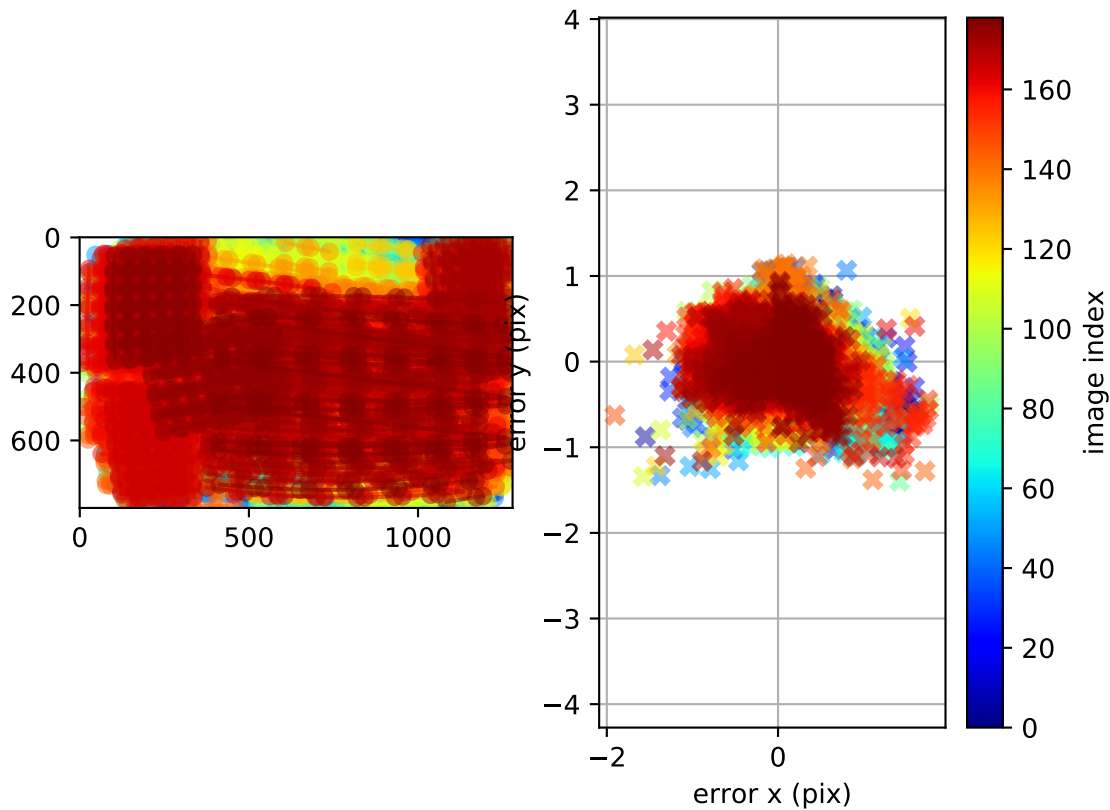
cam2: polar error



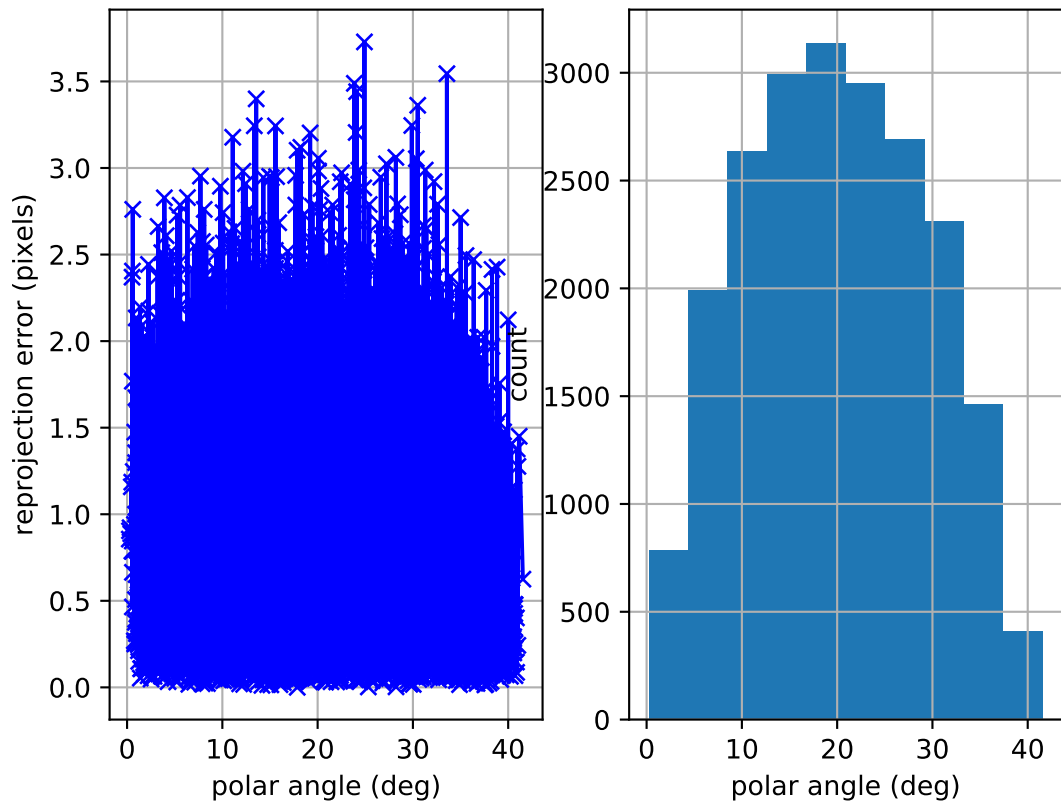
cam2: azimuthal error



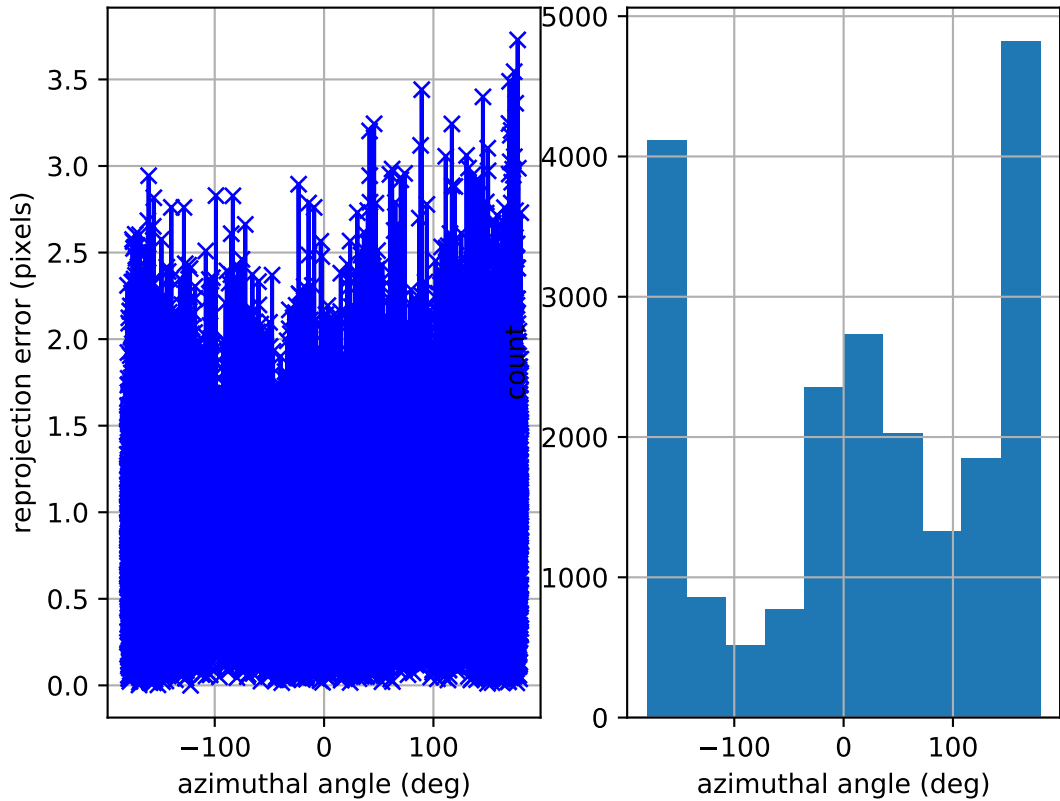
cam2: reprojection errors



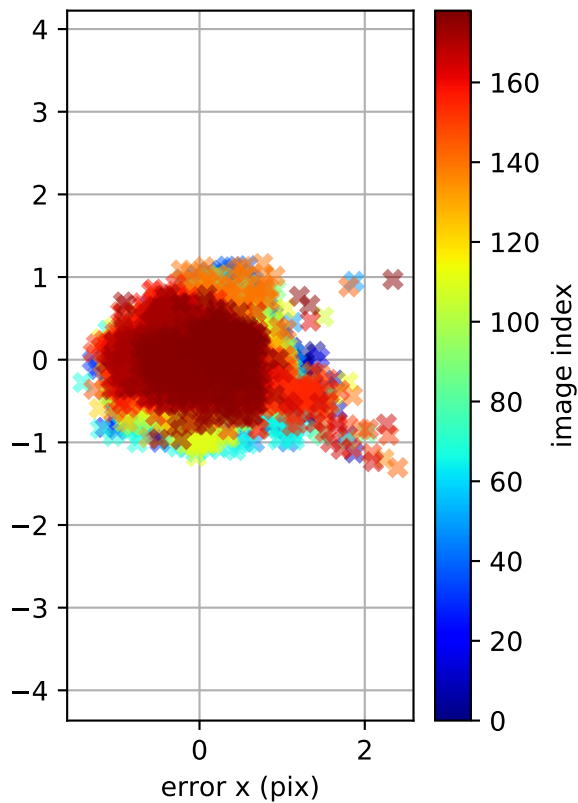
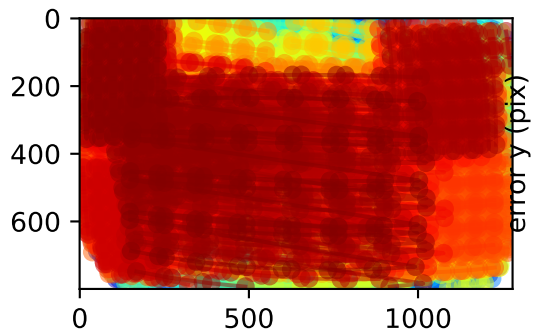
cam3: polar error



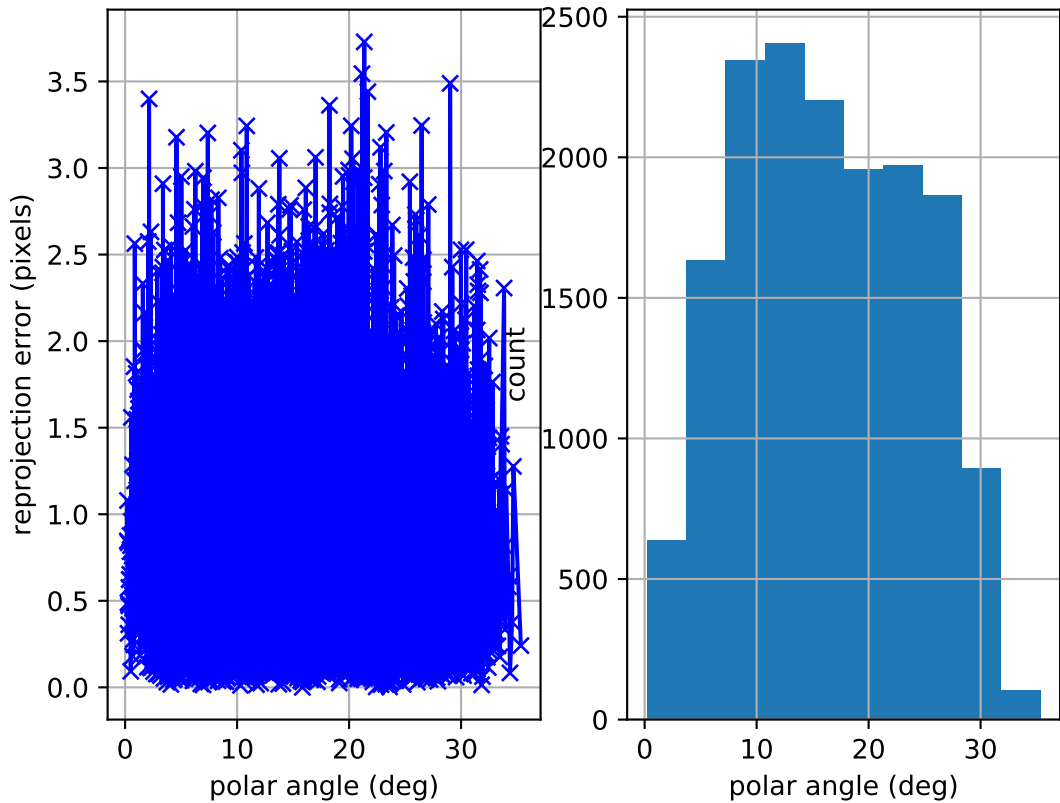
cam3: azimuthal error



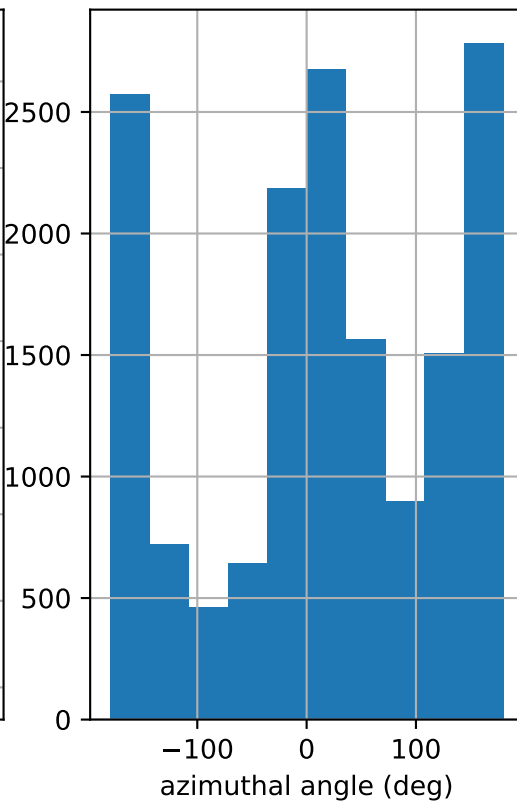
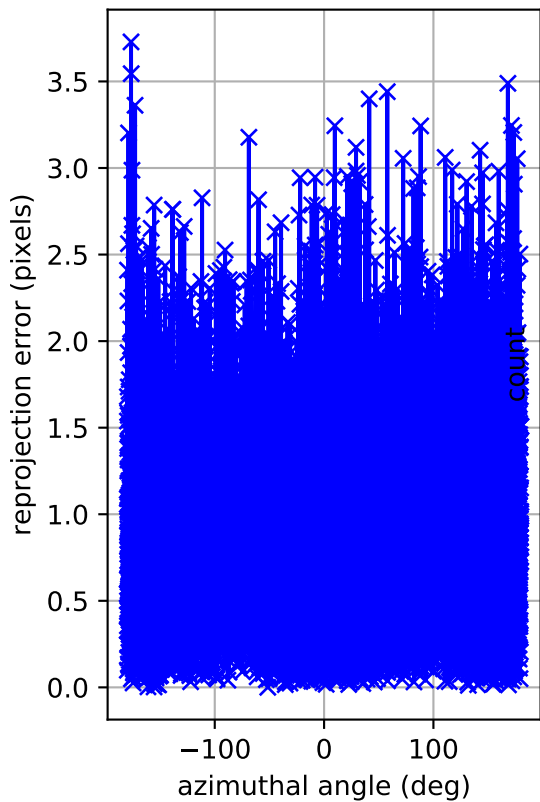
cam3: reprojection errors



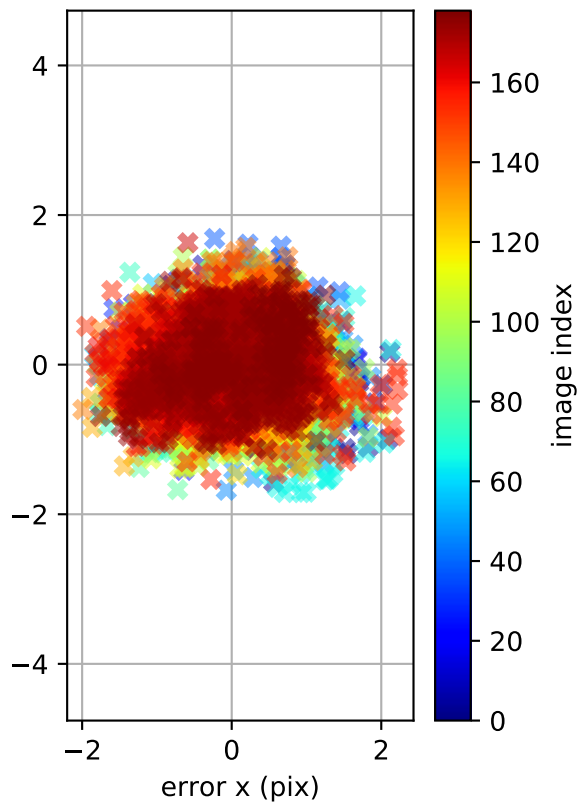
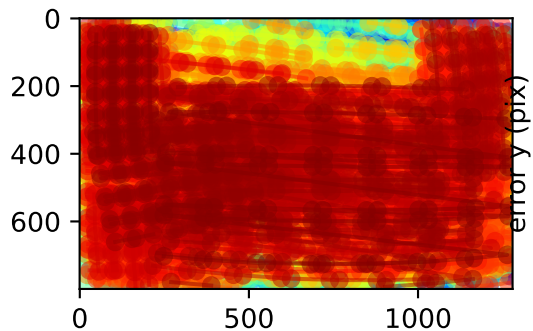
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

