

Calibration results

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Camera-system parameters:

cam0 (/prophesee/left/events):

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

distortion: [-0.04332619 0.08015839 0.00087944 -0.00262166] +- [0.00089989 0.00188903 0.00006867 0.00005363]

projection: [1037.19386674 1035.8444213 629.4409195 368.0727264] +- [0.14561402 0.14406745 0.01422642 0.12631001]

reprojection error: [0.000144, -0.000047] +- [0.543766, 0.390035]

cam1 (/prophesee/right/events):

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

distortion: [-0.05046901 0.08585596 0.00154455 -0.00170228] +- [0.00093541 0.00206198 0.00006597 0.00005238]

projection: [1036.12637943 1035.52022498 630.28001113 370.22438737] +- [0.14522637 0.14173541 0.00357508 0.08989661]

reprojection error: [0.000219, -0.000099] +- [0.555838, 0.422088]

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

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

distortion: [-0.39542241 0.15910193 -0.00034525 0.00094654] +- [0.00047127 0.00077133 0.00004308 0.00003231]

projection: [1060.39769654 1059.93777779 669.0410687 338.0955079] +- [0.1159054 0.11735183 0.00688071 0.1817944]

reprojection error: [0.000234, -0.000284] +- [0.294048, 0.187793]

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

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

distortion: [-0.39361678 0.15293569 -0.00051063 0.00163048] +- [0.00040542 0.00061446 0.00004228 0.00003279]

projection: [1055.69657808 1056.03278964 666.291421 331.25697121] +- [0.11196446 0.11195401 0.01824166 0.17793396]

reprojection error: [0.000230, -0.000431] +- [0.317601, 0.213472]

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

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

distortion: [-0.41736733 0.18973967 -0.00017076 0.0006983] +- [0.00073405 0.00173284 0.00004667 0.00003634]

projection: [1268.42715892 1267.76982675 644.72355796 369.30530722] +- [0.12945389 0.12912124 0.0039586 0.05628132]

reprojection error: [0.000122, 0.000027] +- [0.394403, 0.323104]

baseline T_1_0:

q: [-0.00073641 0.0015364 -0.00038182 0.99999848] +- [0.00011958 0.00006385 0.00003469]

t: [-0.12017793 0.00094723 0.00033655] +- [0.0000415 0.00003862 0.00013079]

baseline T_2_1:

q: [-0.00007902 -0.00256592 -0.0051053 0.99998367] +- [0.00022265 0.00005051 0.00003304]

t: [0.11991525 0.06929575 0.00207649] +- [0.00003504 0.00003299 0.00011634]

baseline T_3_2:

q: [-0.00007065 -0.00271101 0.00016073 0.99999631] +- [0.00025716 0.00004849 0.00002831]

t: [-0.12001603 -0.00008238 0.00193906] +- [0.00002926 0.00002551 0.00009092]

baseline T_4_3:

q: [0.00251648 0.00451104 0.00044551 0.99998656] +- [0.00020052 0.00004343 0.00002811]

t: [0.08890949 0.00615432 0.00269226] +- [0.00002625 0.00002416 0.00008944]

Target configuration

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Type: aprilgrid

Tags:

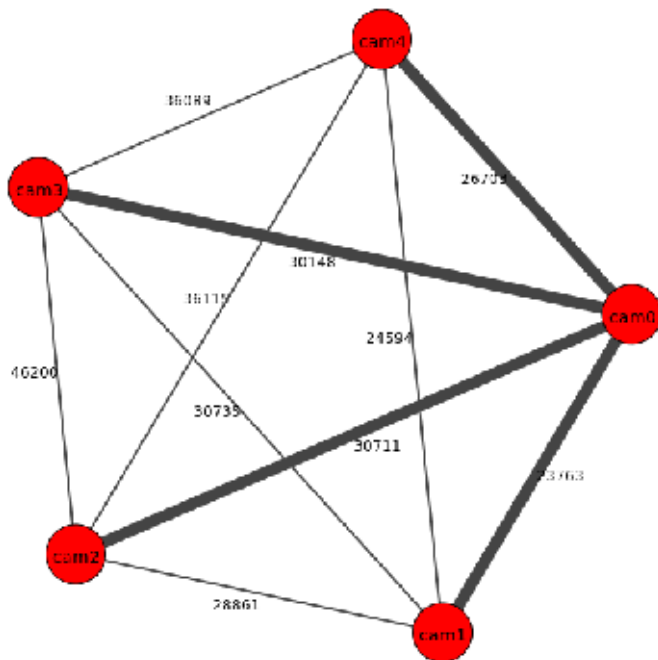
Rows: 5

Cols: 7

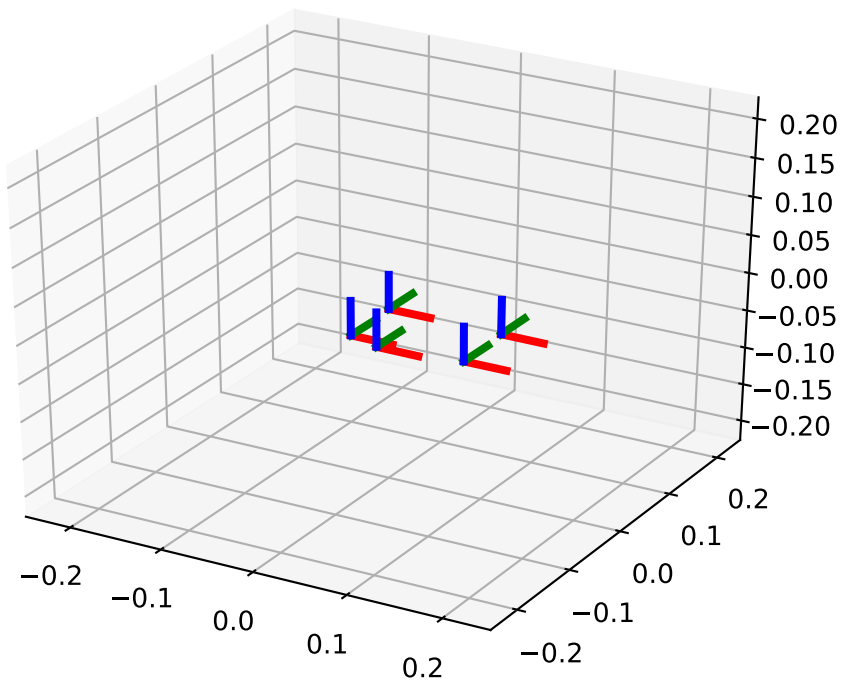
Size: 0.04 [m]

Spacing 0.01 [m]

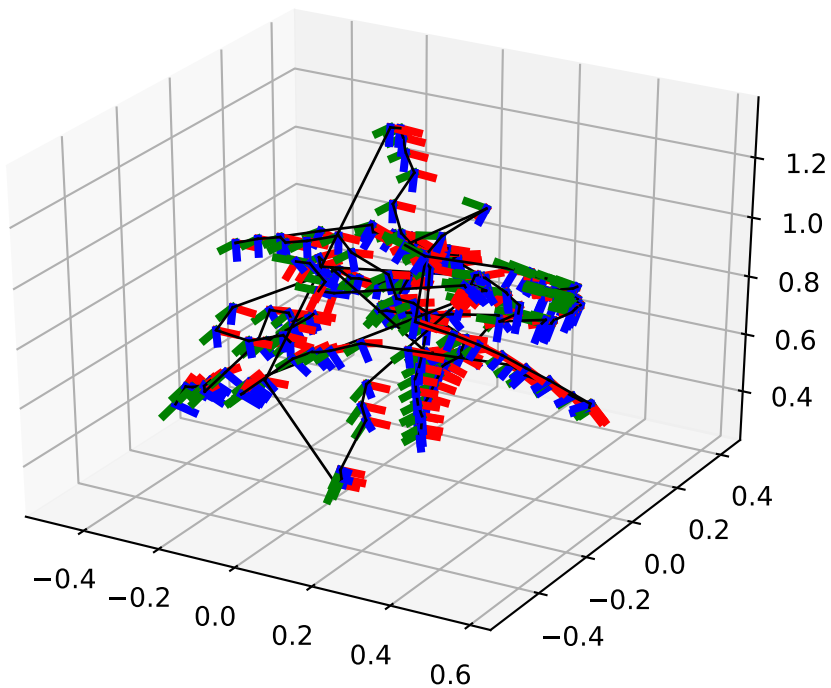
Inter-camera observations graph (edge weight=#mutual obs.)



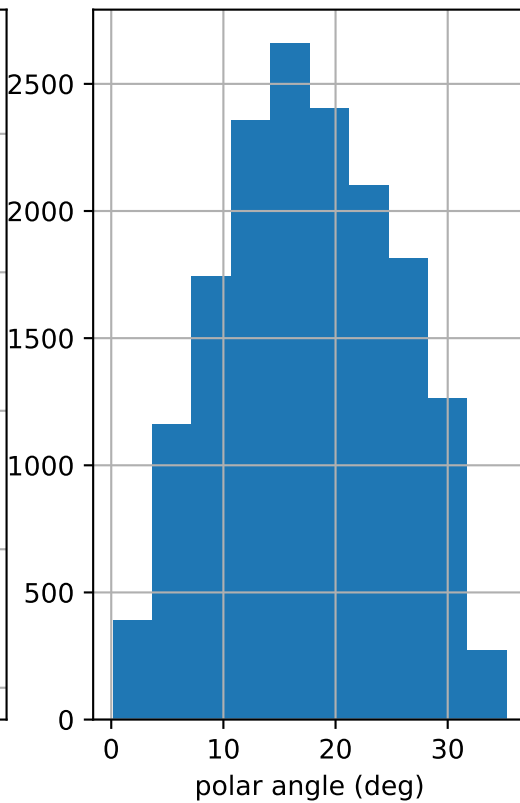
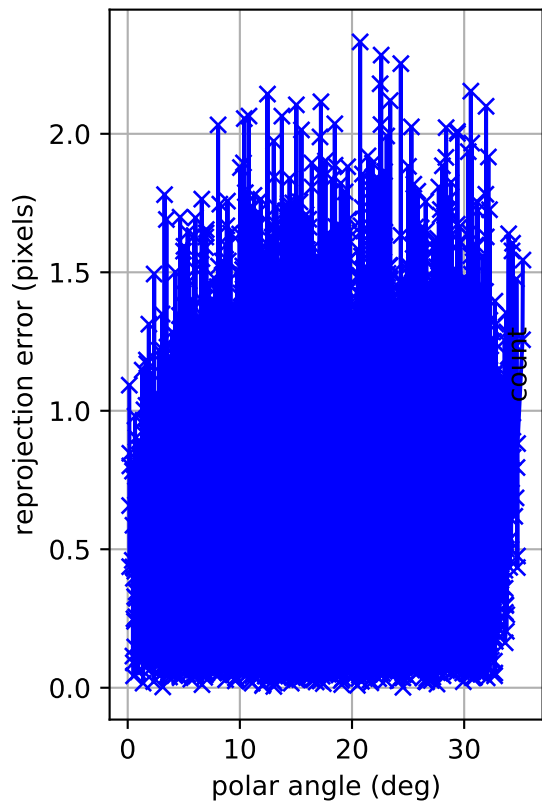
camera system



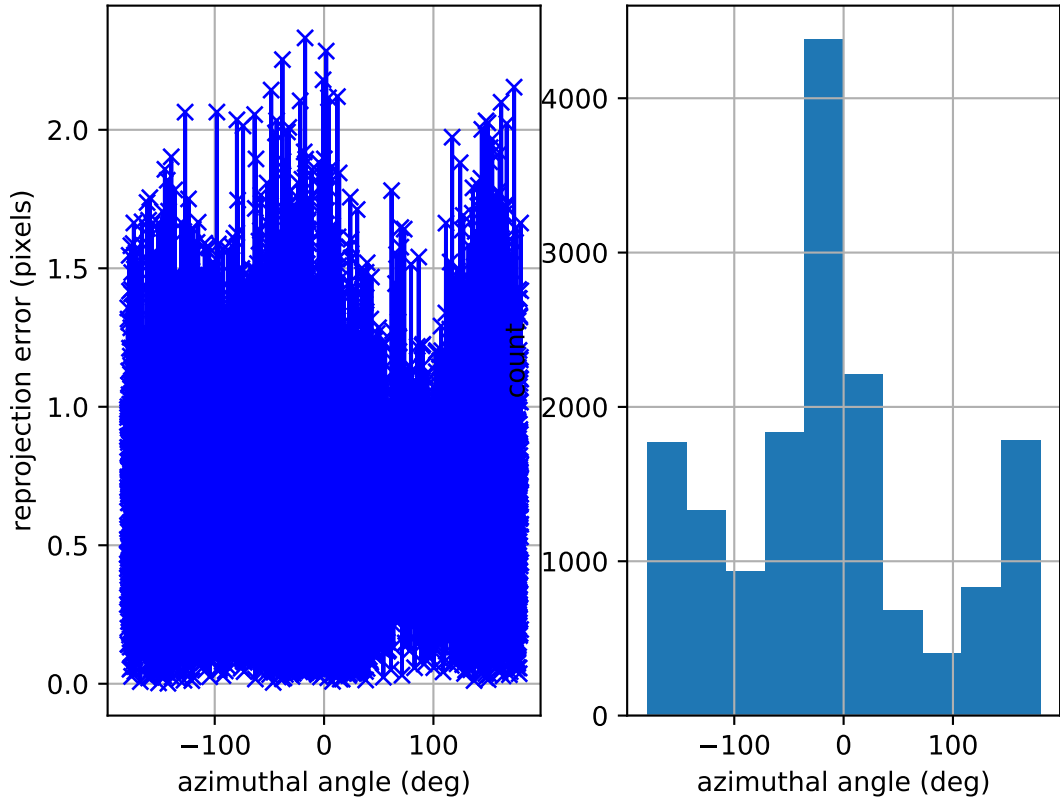
cam0: estimated poses



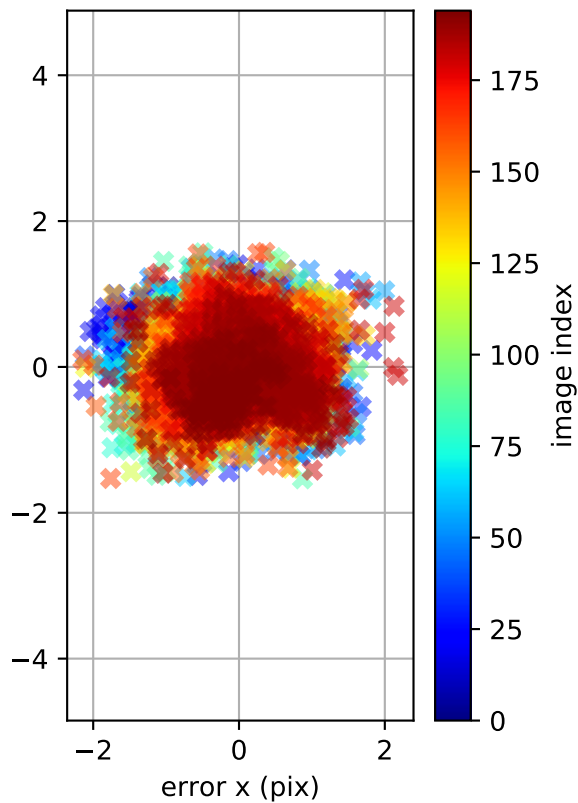
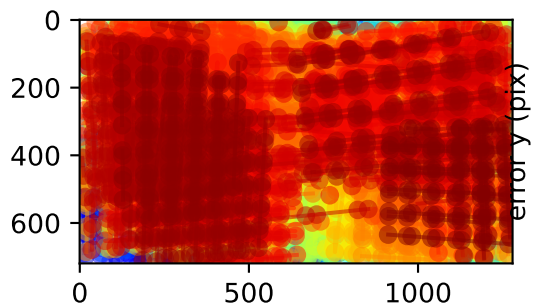
cam0: polar error



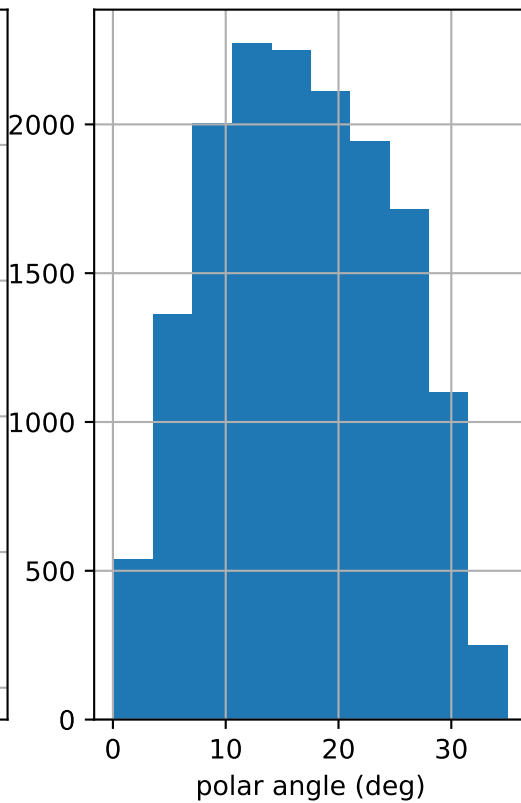
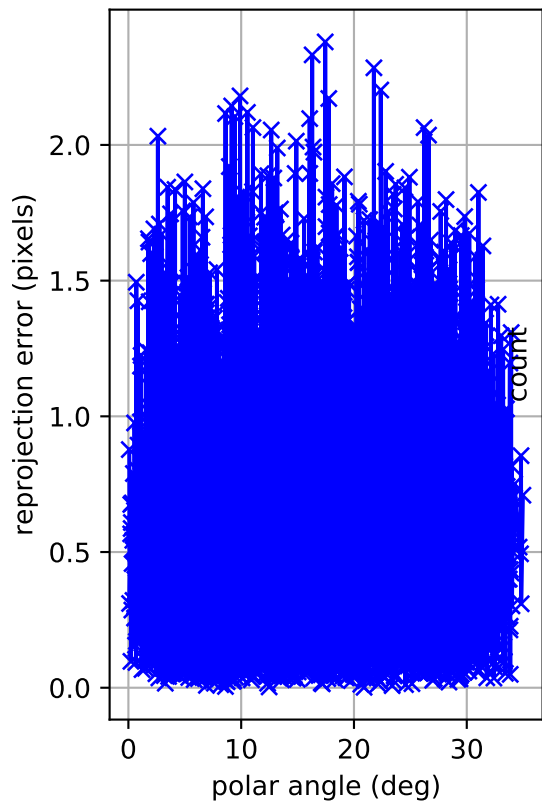
cam0: azimuthal error



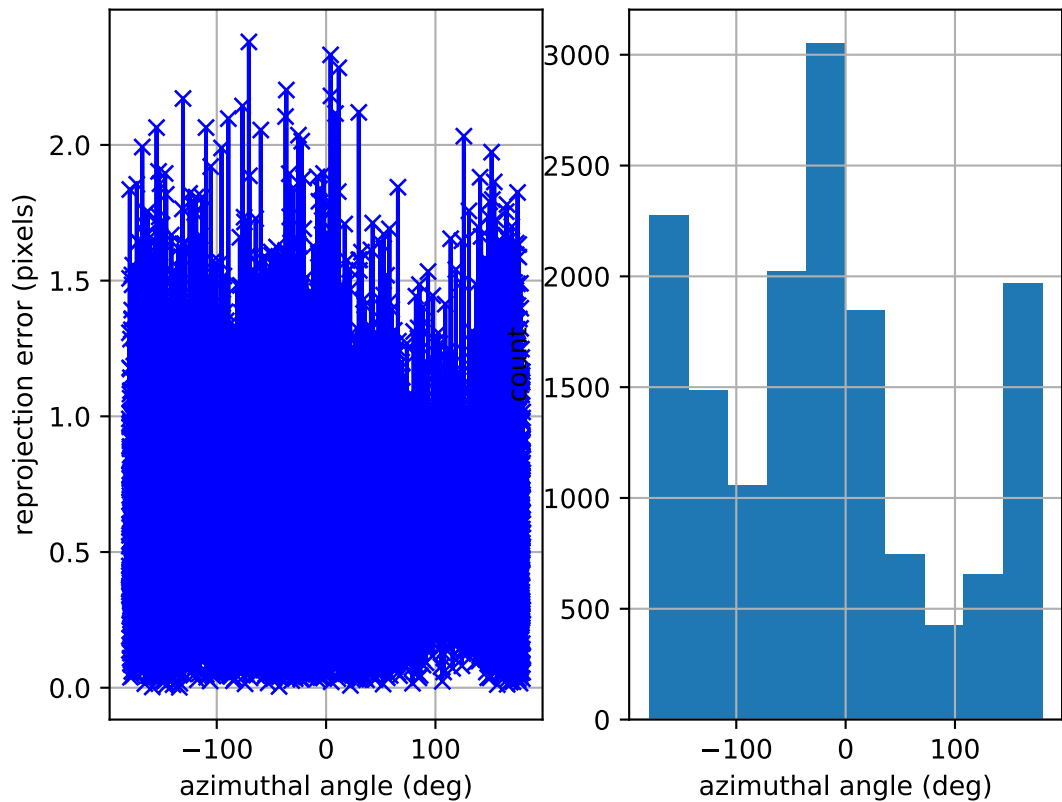
cam0: reprojection errors



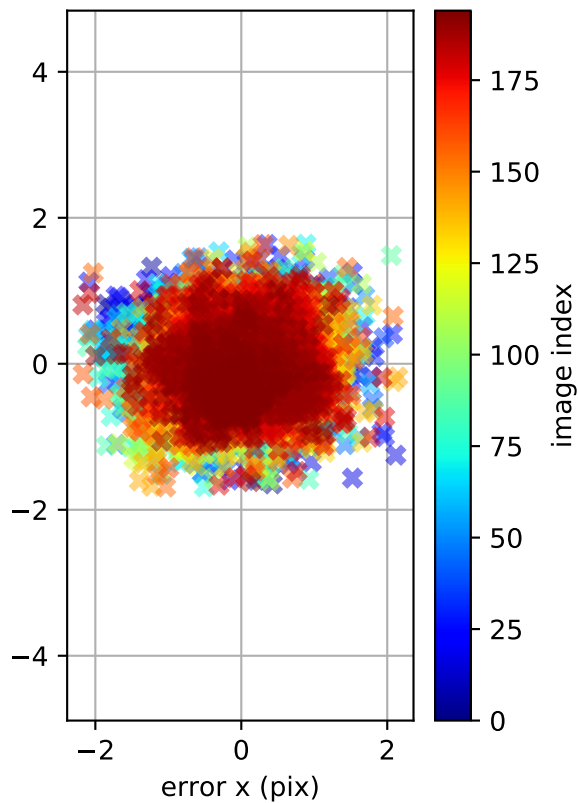
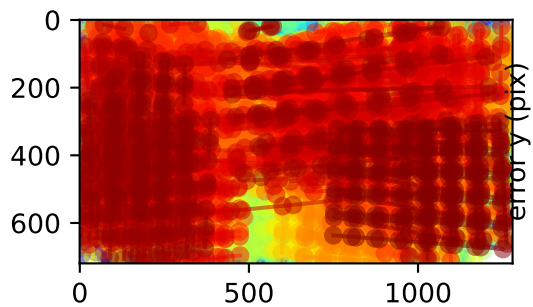
cam1: polar error



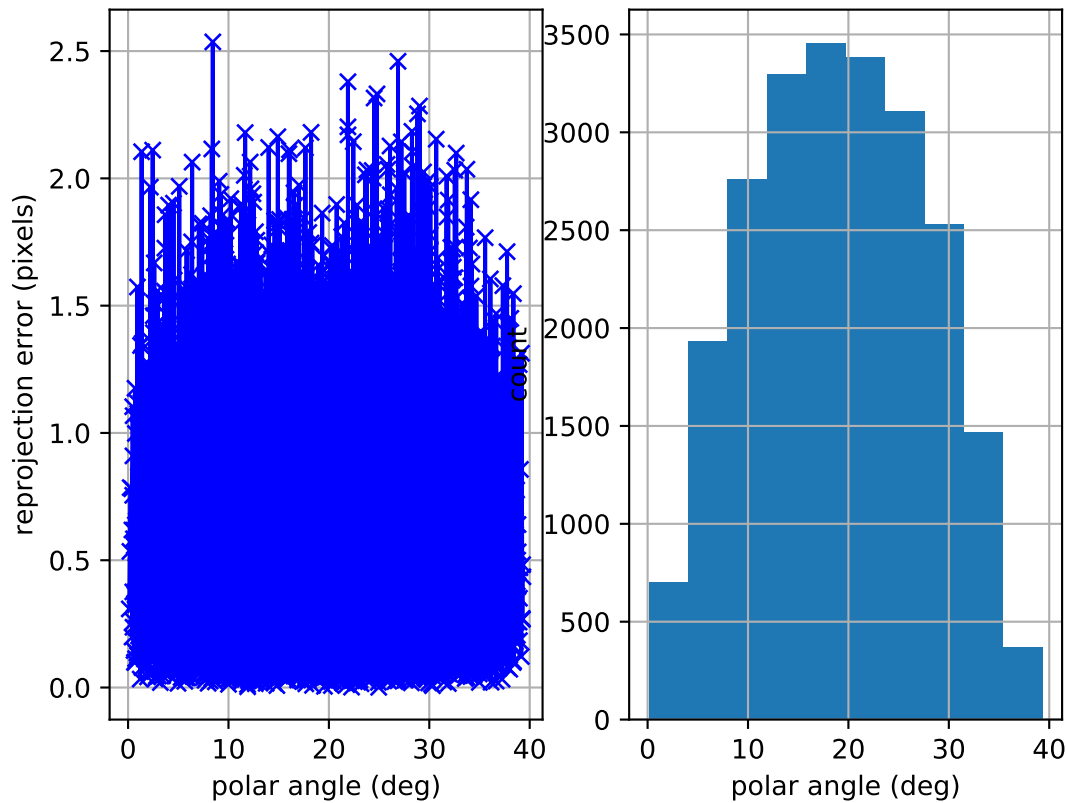
cam1: azimuthal error



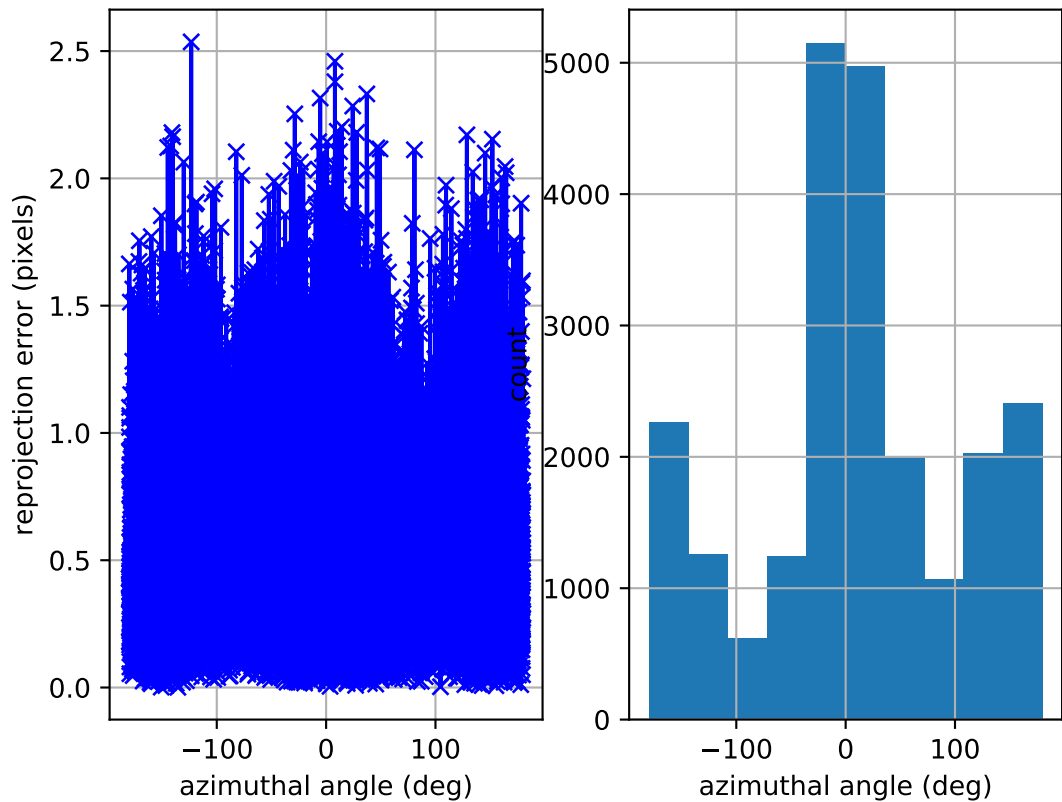
cam1: reprojection errors



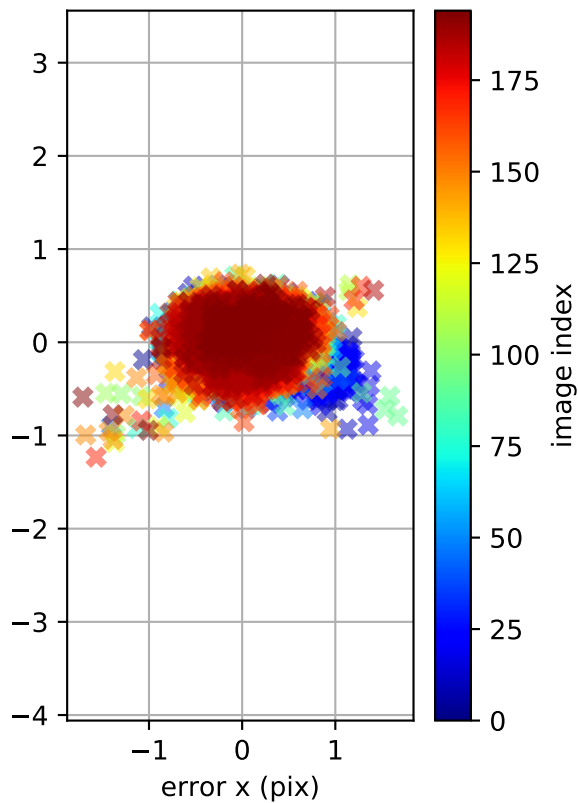
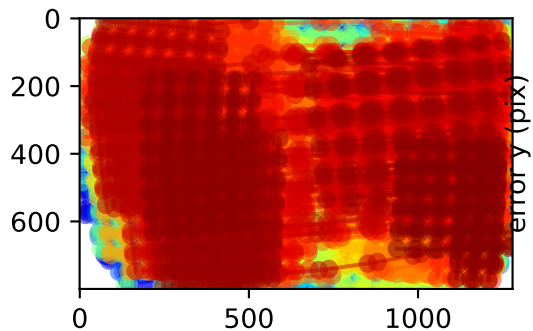
cam2: polar error



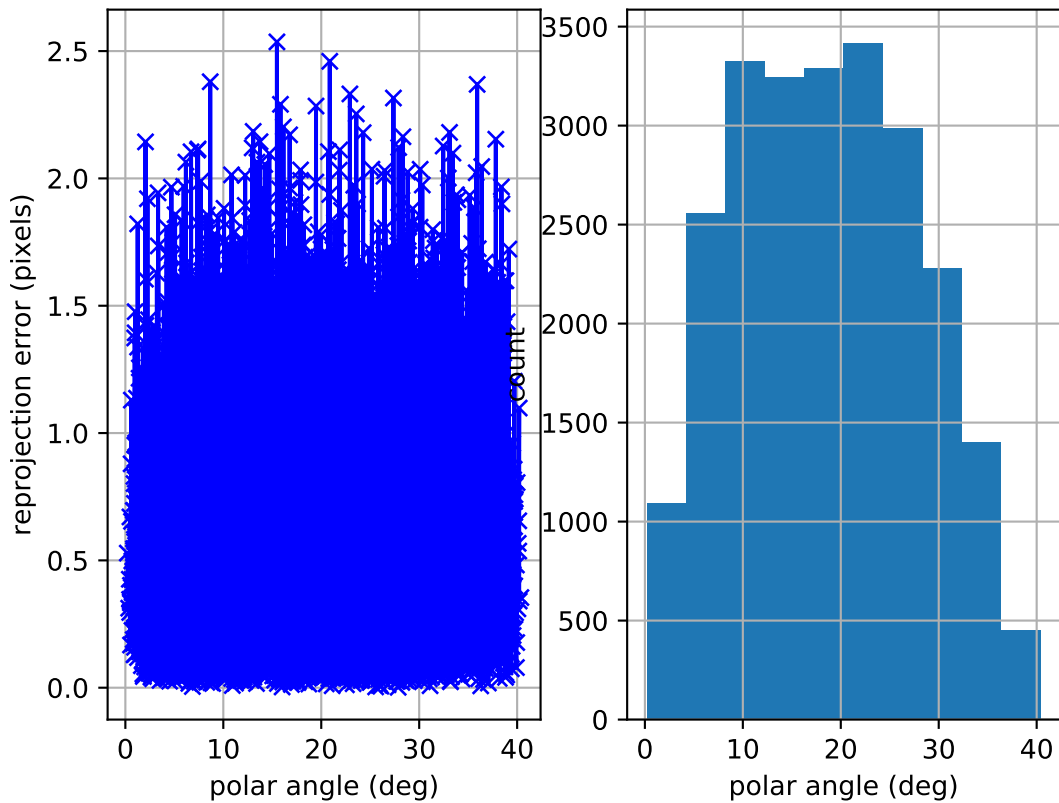
cam2: azimuthal error



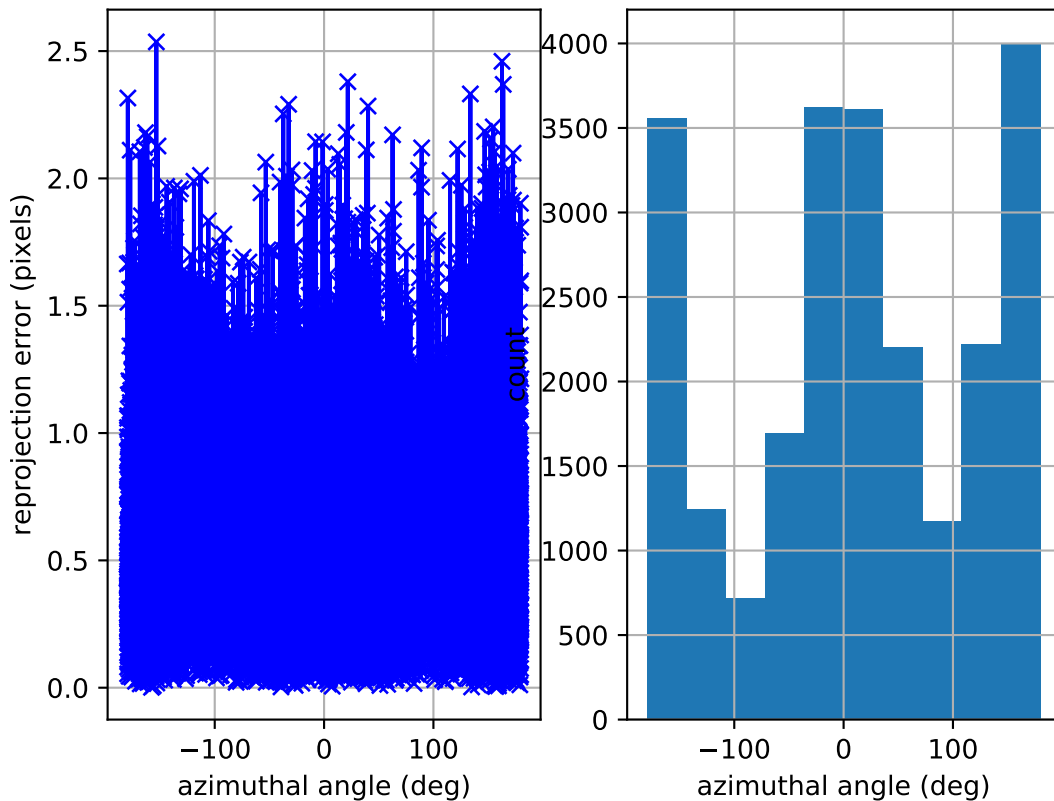
cam2: reprojection errors



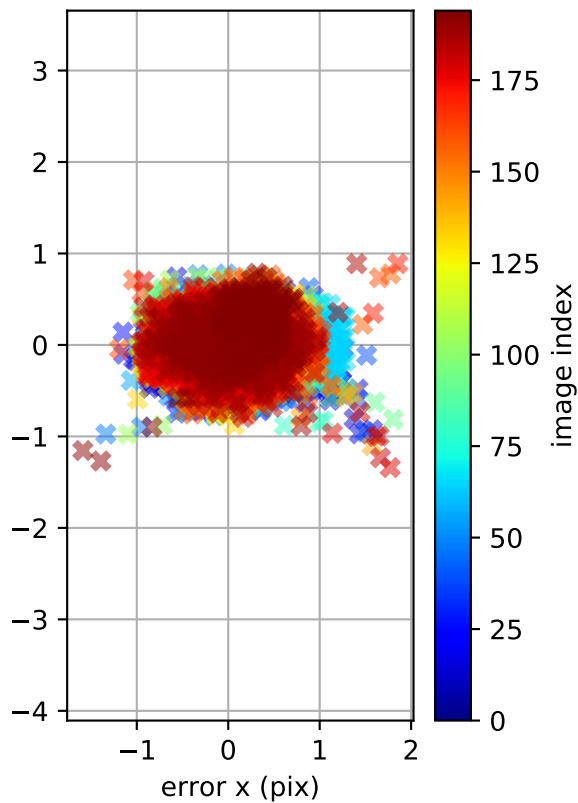
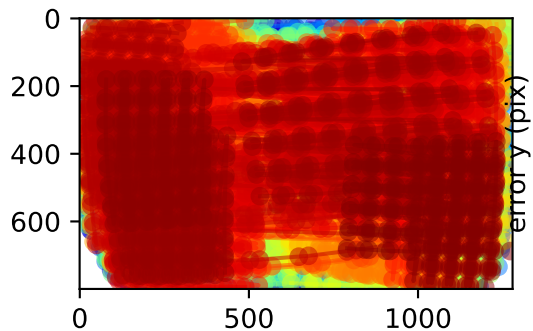
cam3: polar error



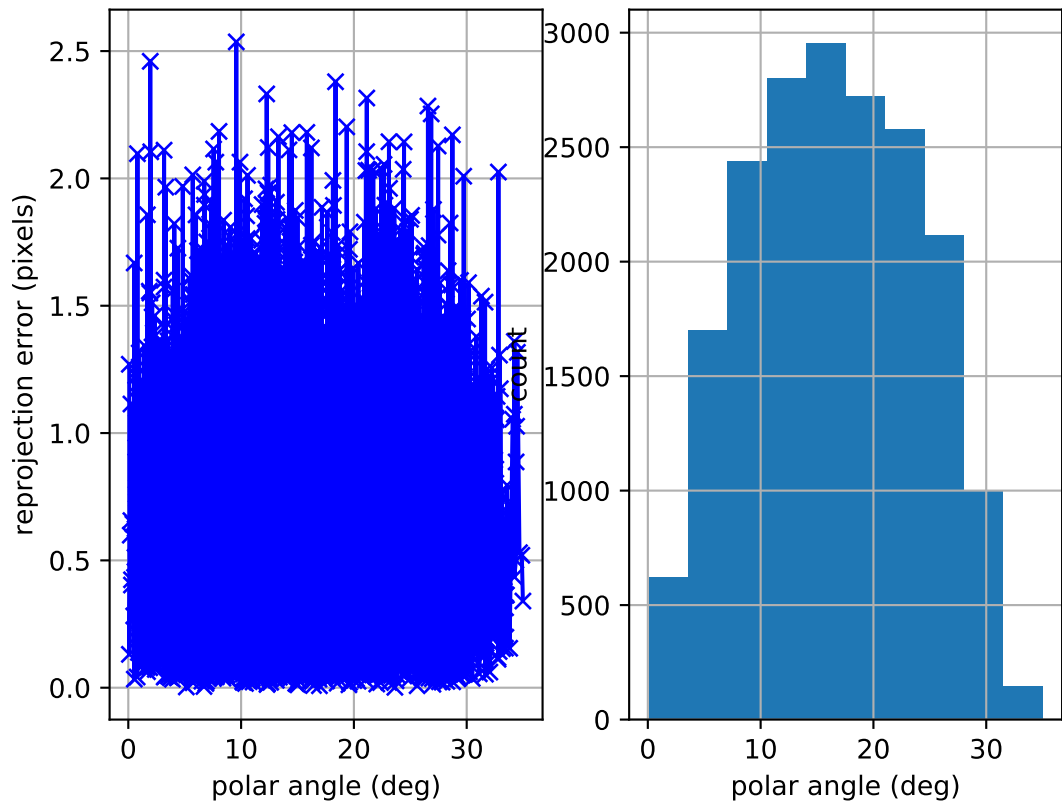
cam3: azimuthal error



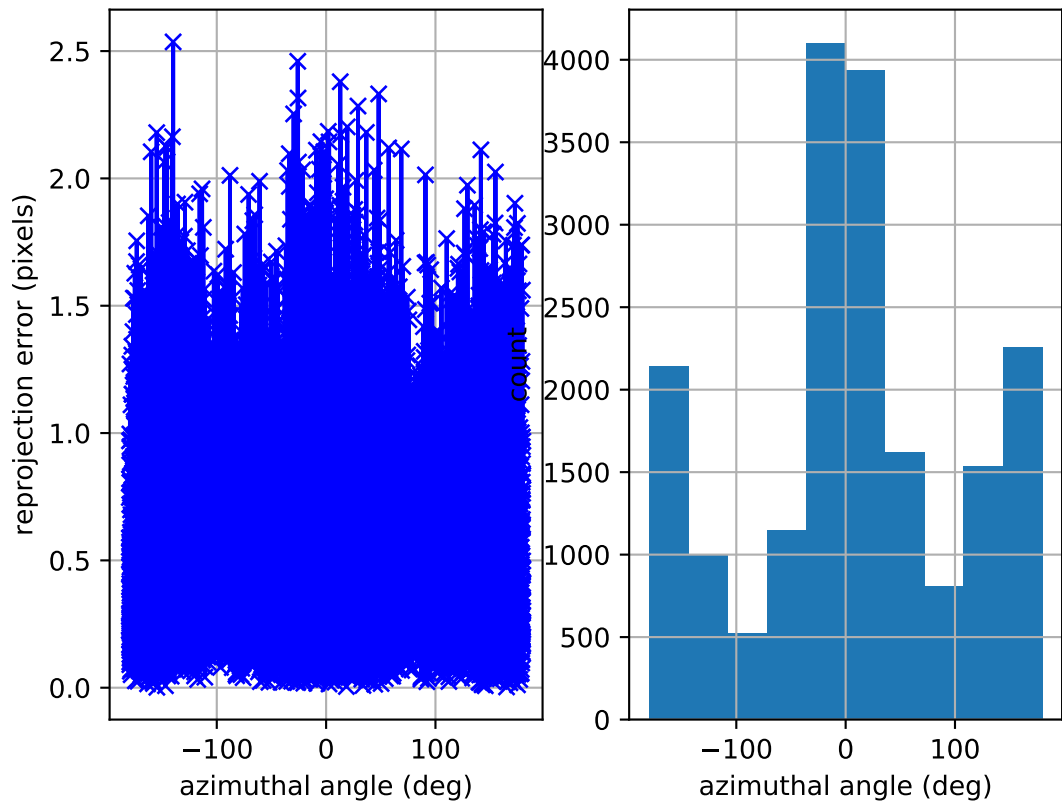
cam3: reprojection errors



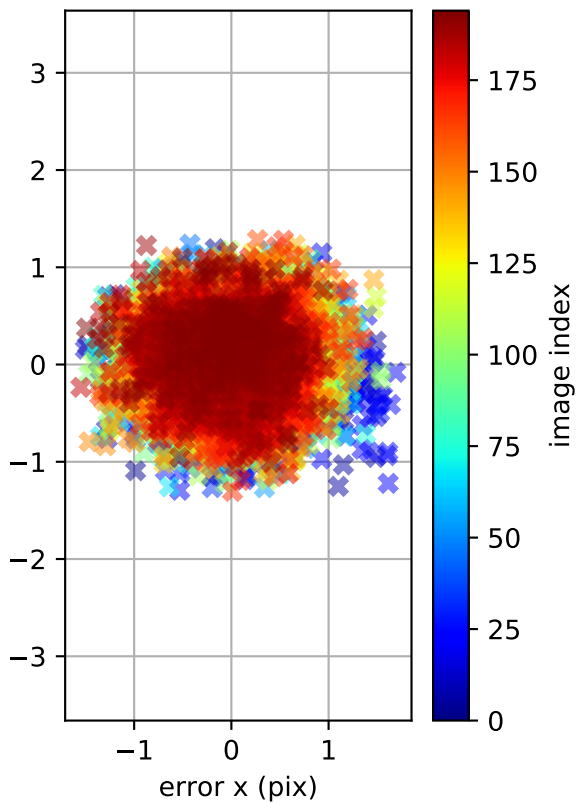
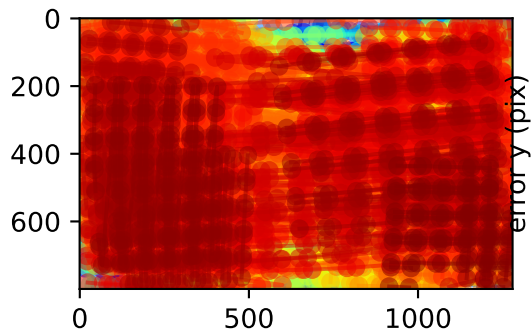
cam4: polar error



cam4: azimuthal error



cam4: reprojection errors



Location of removed outlier corners

