

Calibration results

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Camera-system parameters:

cam0 (/camera/stereo_left/image_raw):

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

distortion: [-0.24392356 0.07744357 0.00000143 0.00145111] +- [0.00197472 0.00408979 0.00015995 0.00016617]

projection: [888.78858354 890.45671203 484.81627762 286.10459457] +- [0.21295416 0.22475227 0.55099854 1.23607891]

reprojection error: [0.000005, 0.000445] +- [0.621645, 0.561407]

cam1 (/camera/stereo_right/image_raw):

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

distortion: [-0.2517624 0.09918184 0.0005656 0.00043993] +- [0.00195646 0.00436574 0.00015167 0.00015498]

projection: [889.64642747 890.85673193 482.61336409 299.41248536] +- [0.22662559 0.24398099 0.538617 1.23171678]

reprojection error: [0.000207, 0.000432] +- [0.657518, 0.554908]

baseline T_1 0:

q: [-0.003062 0.00007539 0.00152012 0.99999415] +- [0.00079842 0.00122868 0.0001022]

t: [-0.2144652 0.0011504 0.00022603] +- [0.00011134 0.00010862 0.00046162]

Target configuration

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Type: aprilgrid

Tags:

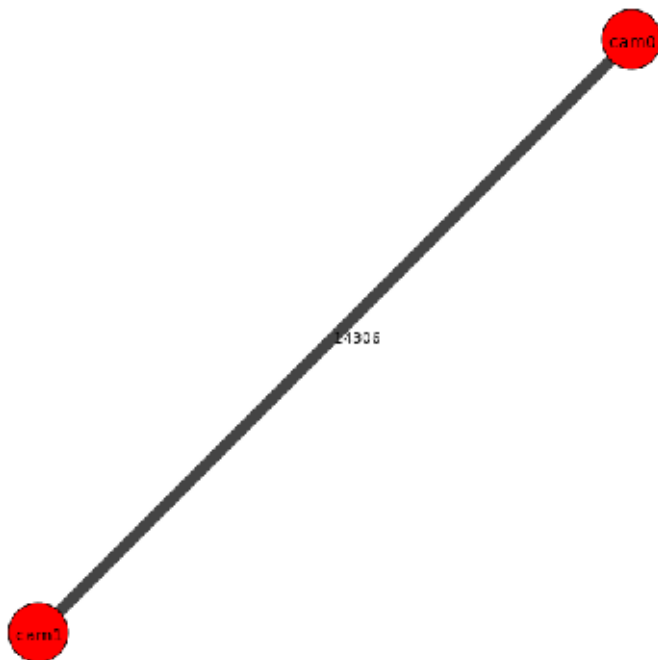
Rows: 6

Cols: 6

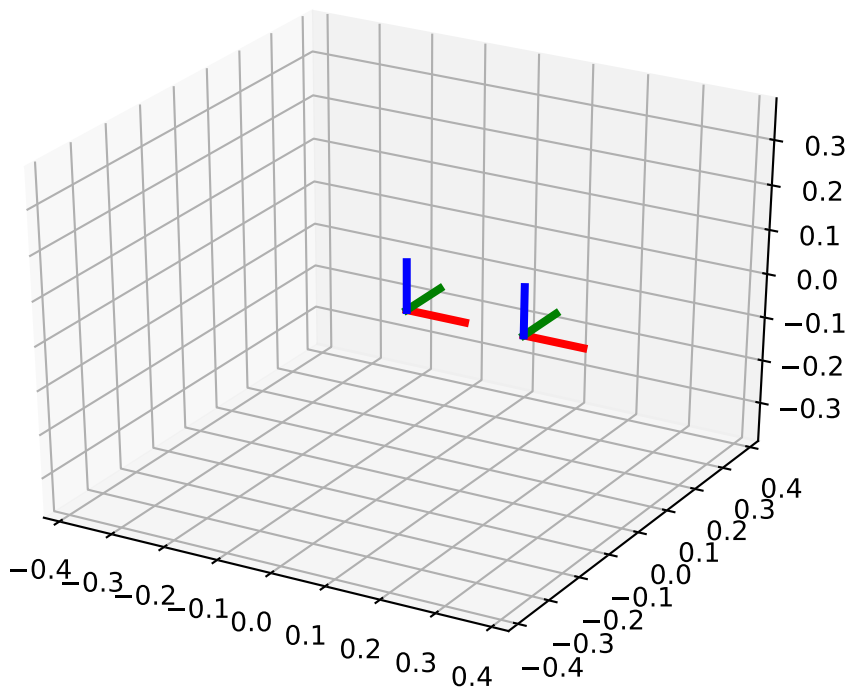
Size: 0.088 [m]

Spacing 0.026399999999999996 [m]

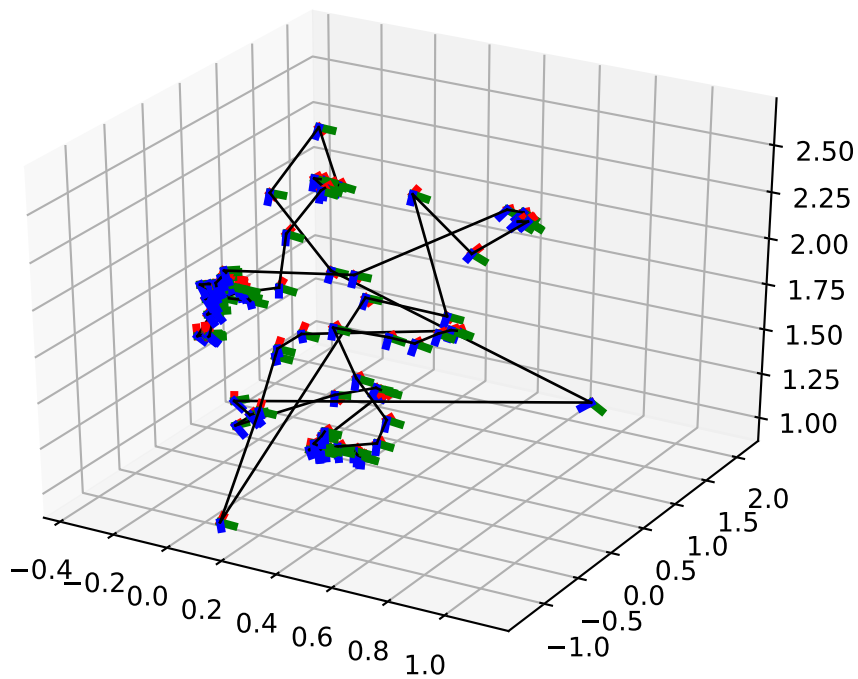
Inter-camera observations graph (edge weight=#mutual obs.)



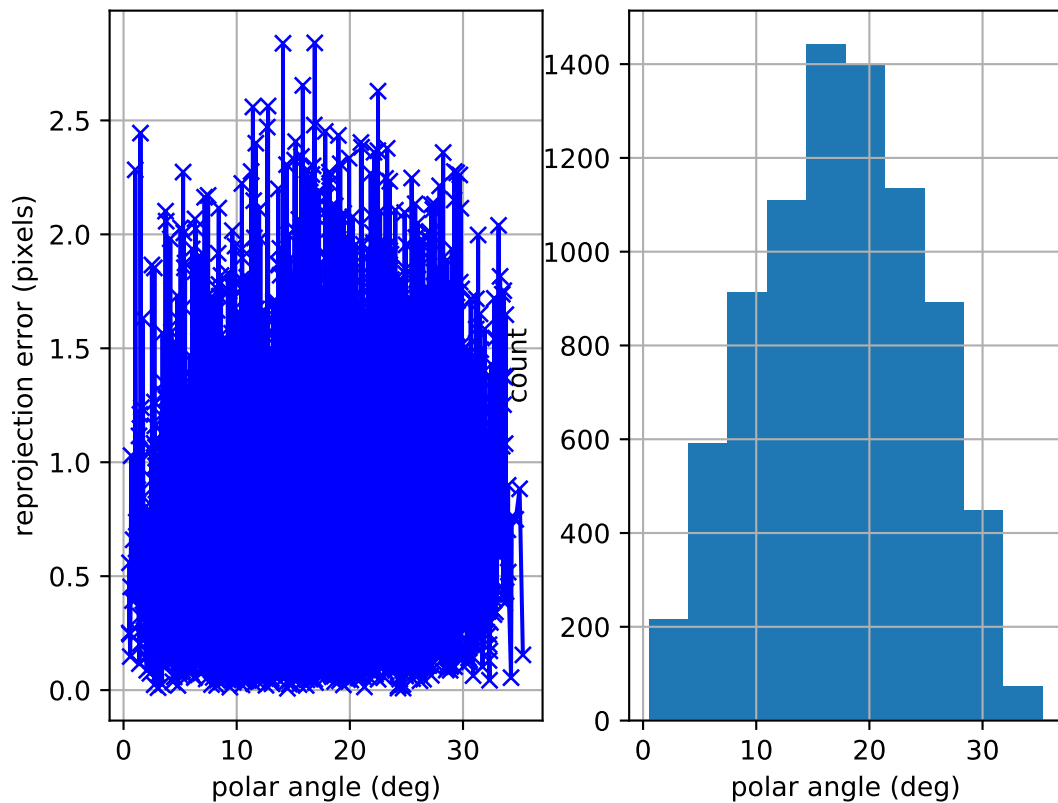
camera system



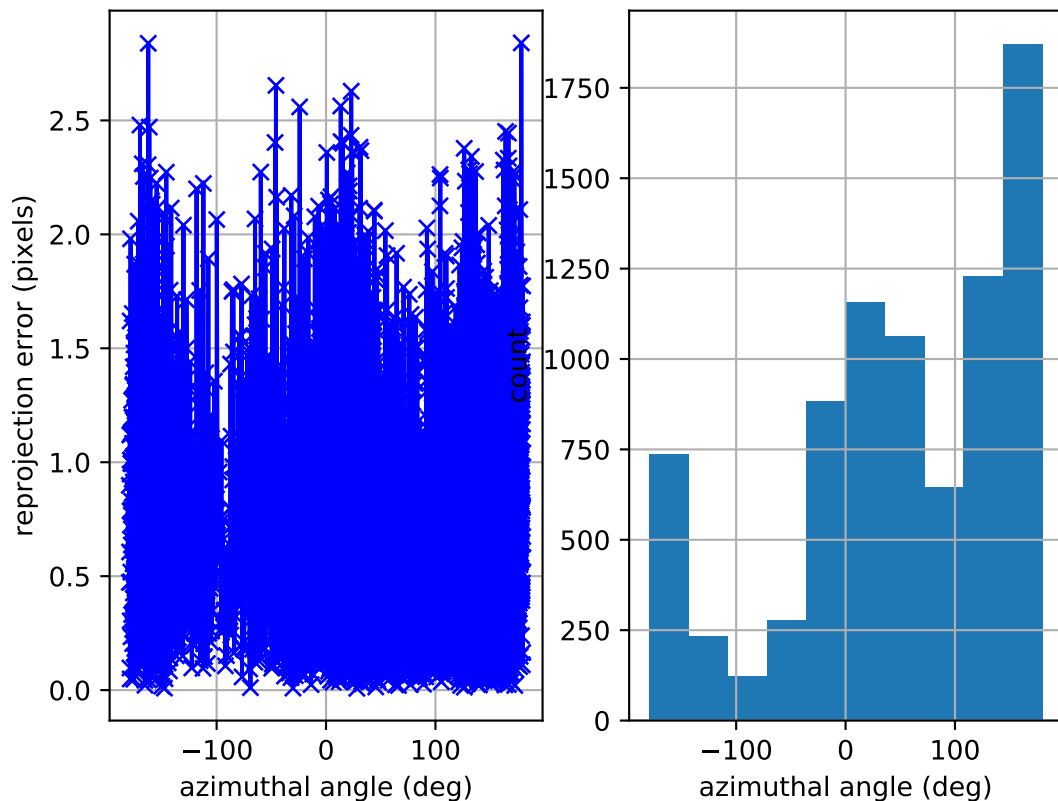
cam0: estimated poses



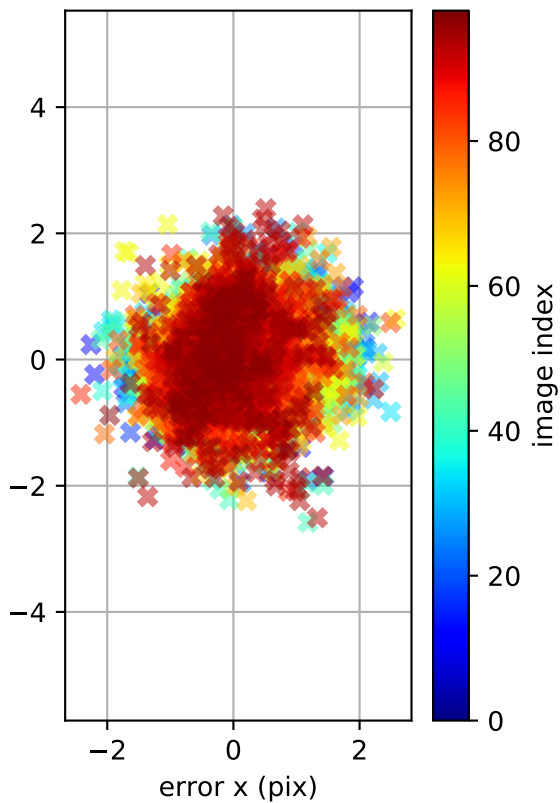
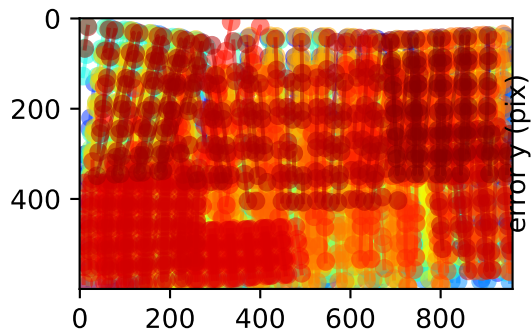
cam0: polar error



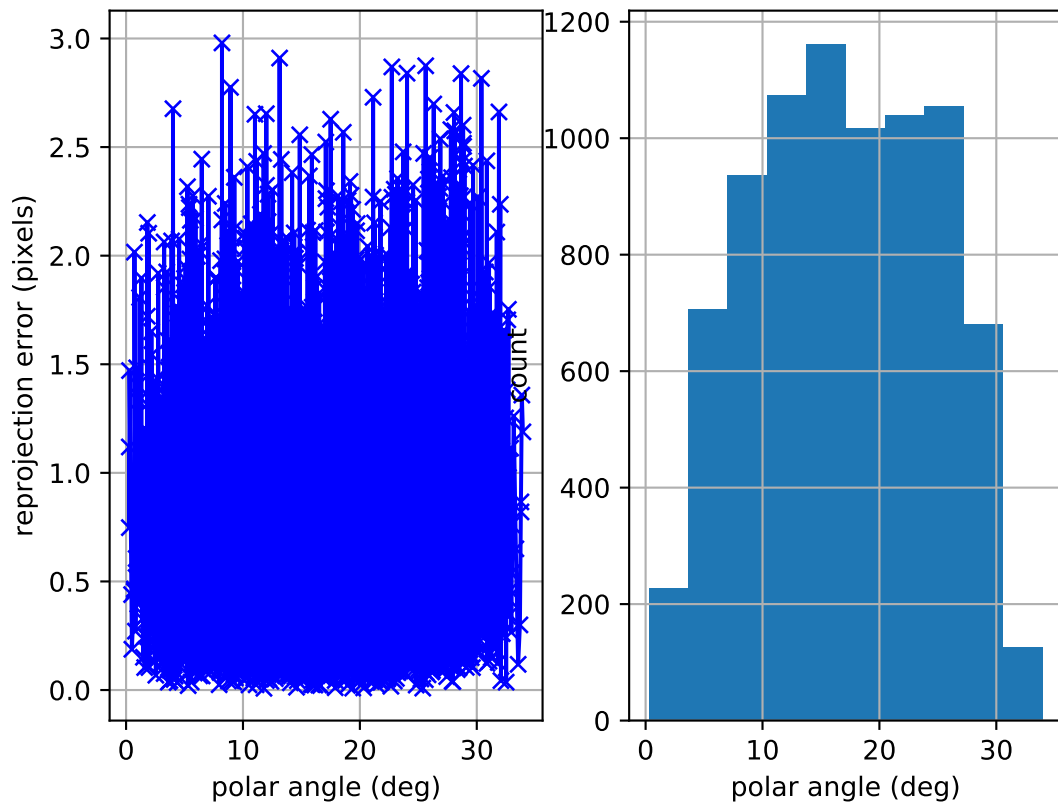
cam0: azimuthal error



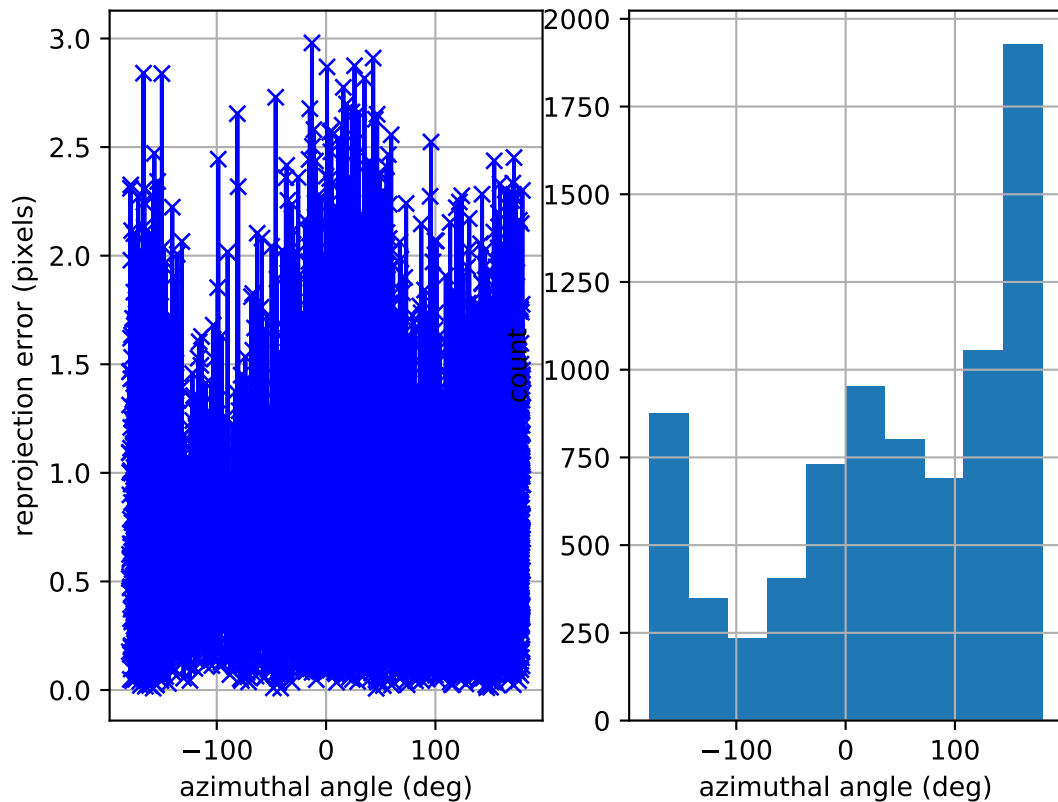
cam0: reprojection errors



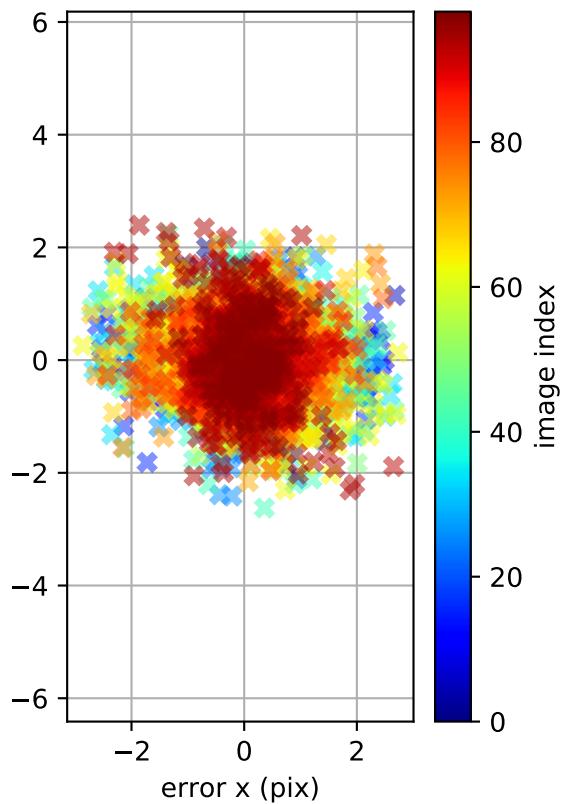
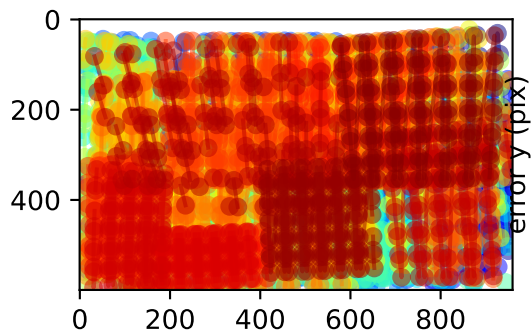
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

