

Calibration results

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Camera-system parameters:

cam0 (/camera/camera/infra1/image_rect_raw):

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

distortion: [0.01494067 -0.00483956 -0.00100571 0.00282766] +- [0.00167927 0.00235484 0.00031129 0.00036528]

projection: [387.73934796 387.90330085 323.22455 239.99773536] +- [0.32748487 0.31545084 0.41010829 0.35529094]

reprojection error: [0.000003, -0.000000] +- [0.299739, 0.248443]

cam1 (/camera/camera/infra2/image_rect_raw):

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

distortion: [0.01839345 -0.00852912 -0.00091126 0.00221681] +- [0.00146664 0.00169322 0.00029948 0.00036755]

projection: [388.27546682 388.02520701 320.33991509 240.61482733] +- [0.33421843 0.31869024 0.40028621 0.35378584]

reprojection error: [-0.000003, 0.000000] +- [0.272035, 0.241480]

baseline T_1_0:

q: [-0.00070503 -0.00428035 0.00019208 0.99999057] +- [0.00091217 0.00115238 0.00013498]

t: [-0.04989244 -0.00001674 0.00003011] +- [0.00002383 0.0000221 0.00007039]

Target configuration

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Type: aprilgrid

Tags:

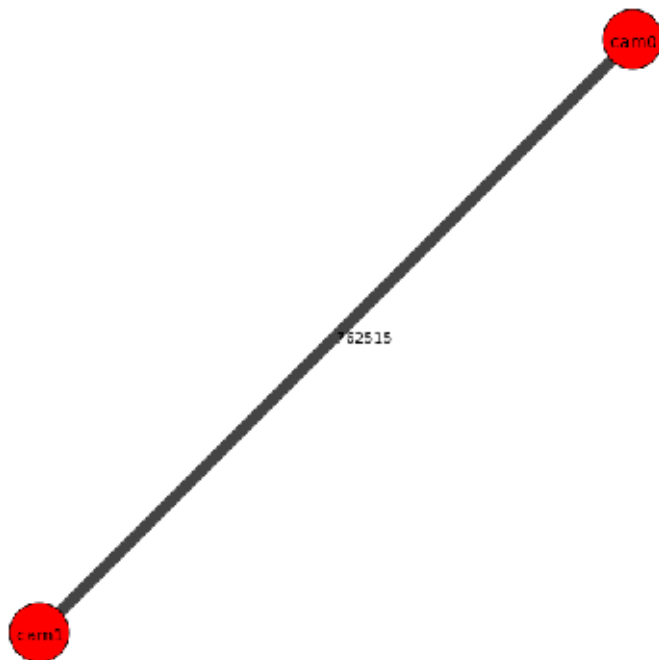
Rows: 6

Cols: 6

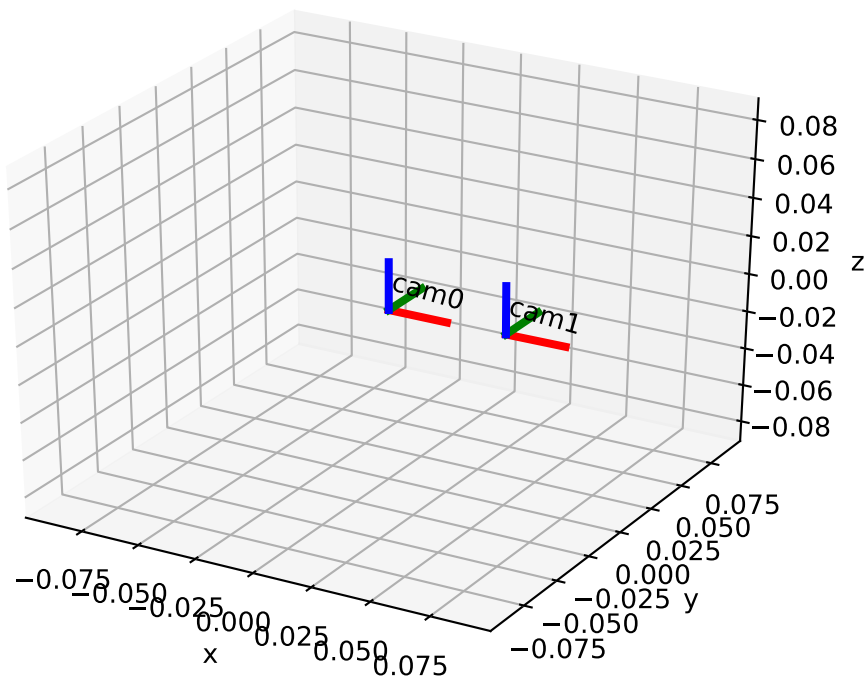
Size: 0.0205 [m]

Spacing 0.00630006 [m]

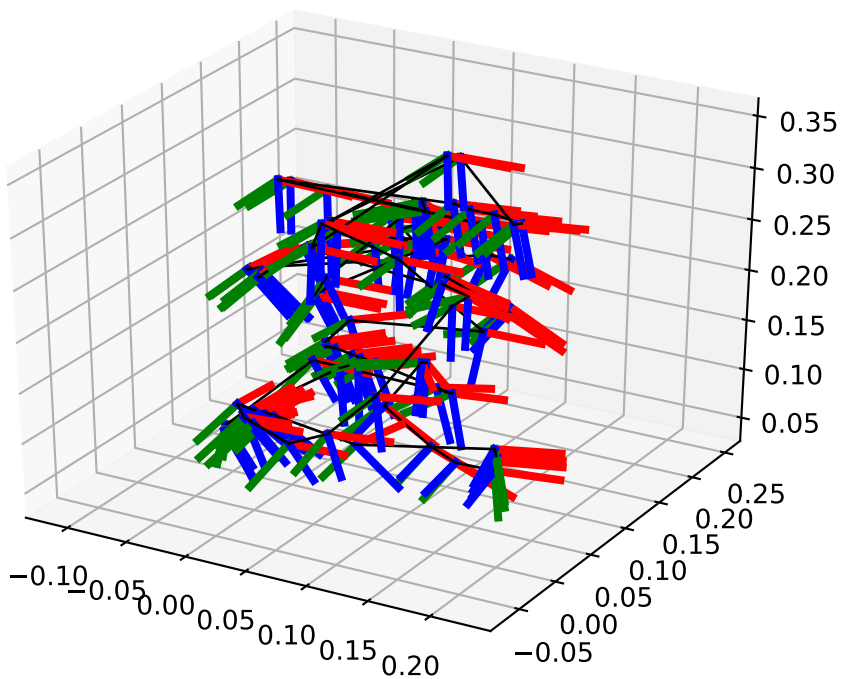
Inter-camera observations graph (edge weight=#mutual obs.)



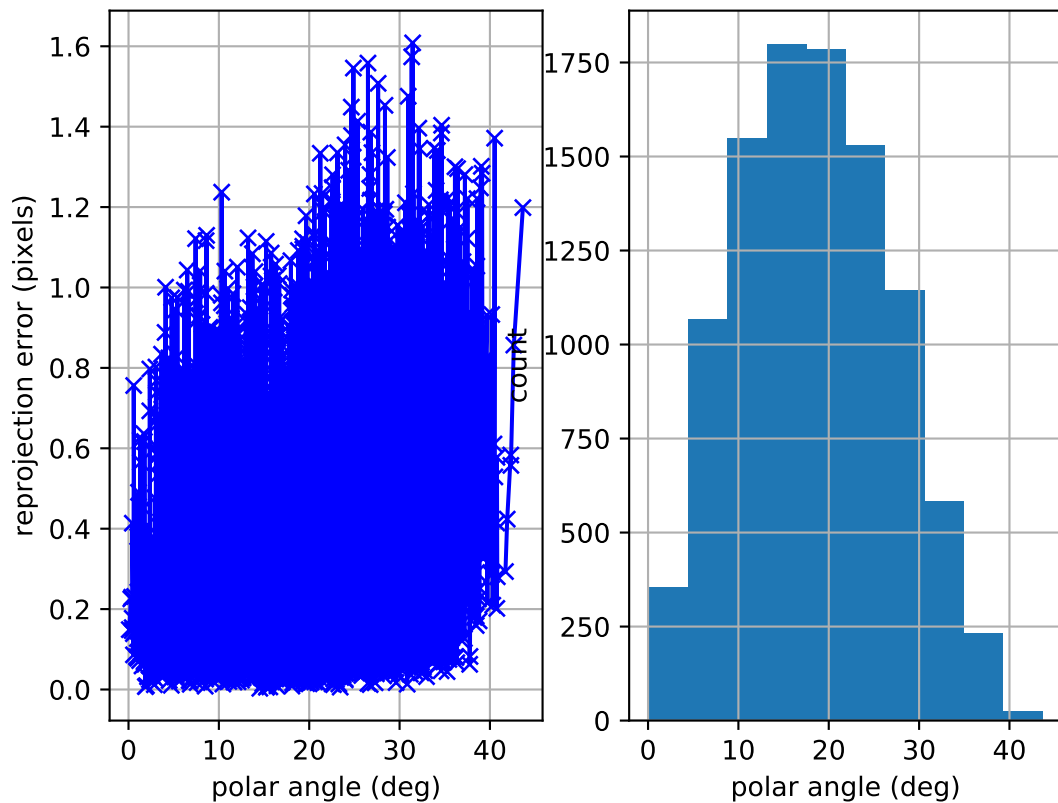
camera system



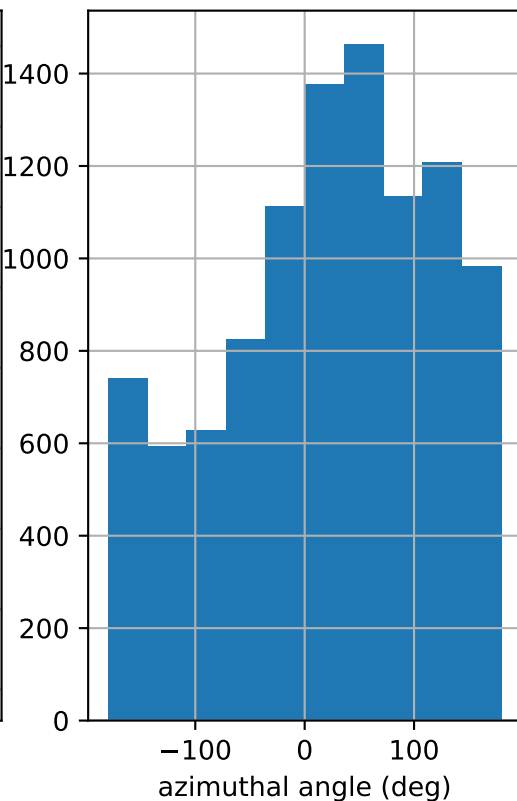
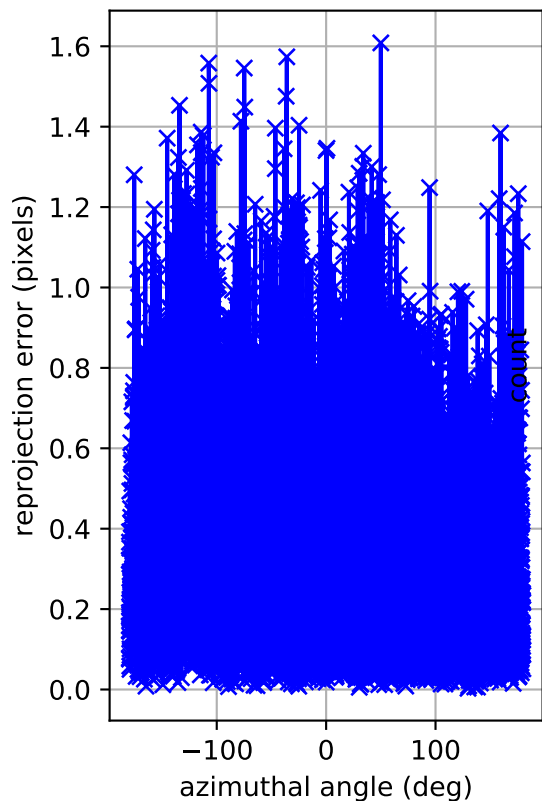
cam0: estimated poses



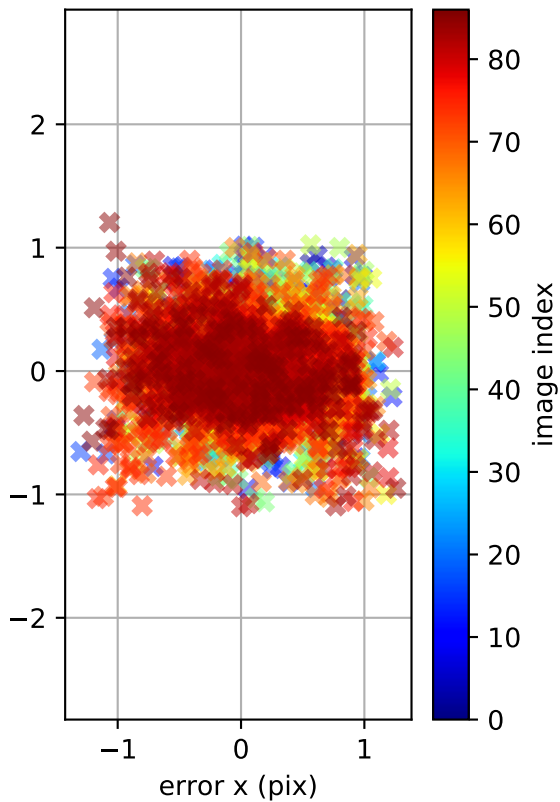
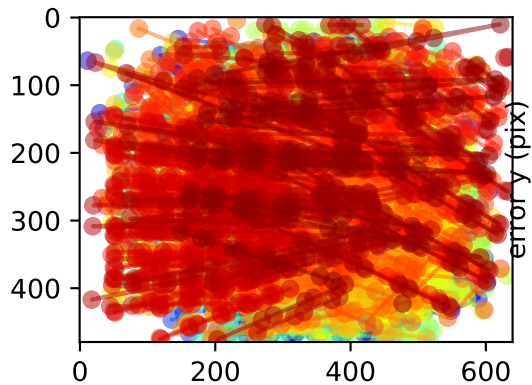
cam0: polar error



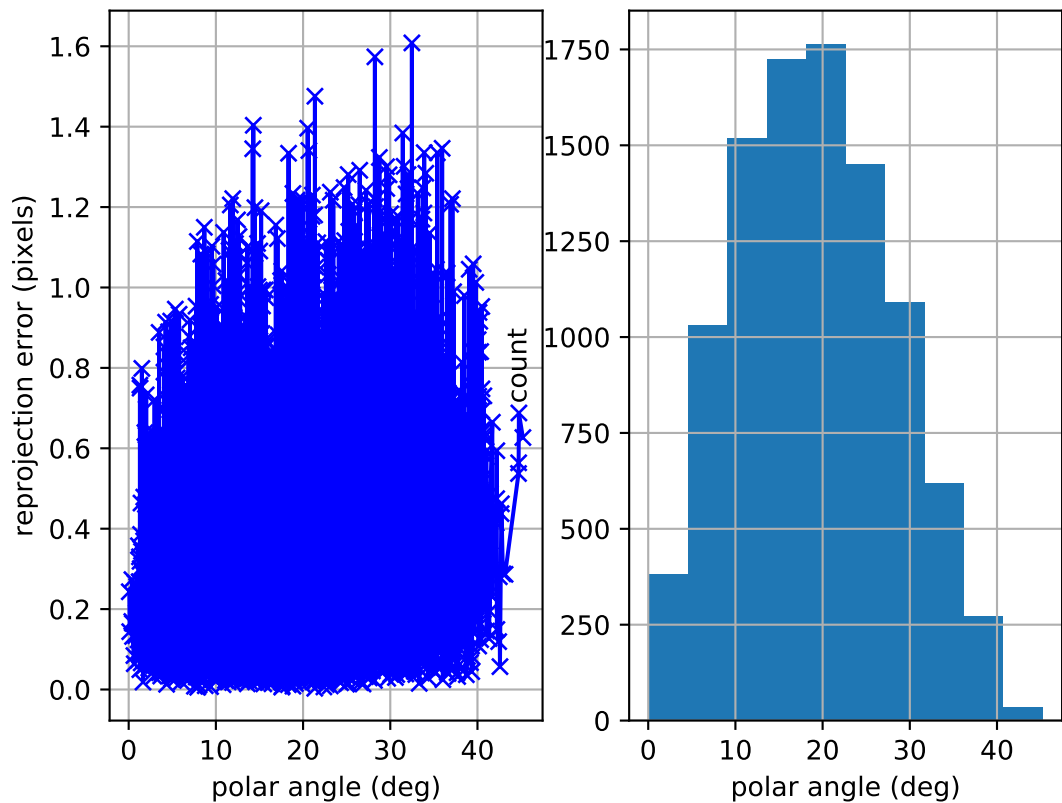
cam0: azimuthal error



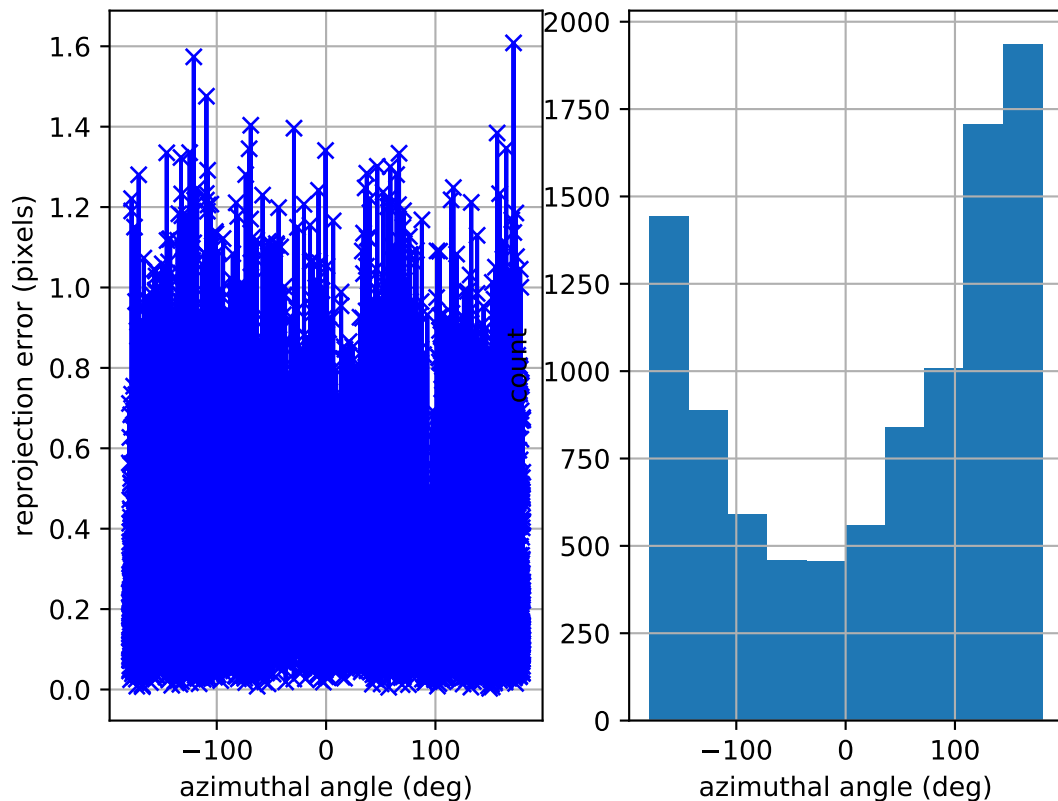
cam0: reprojection errors



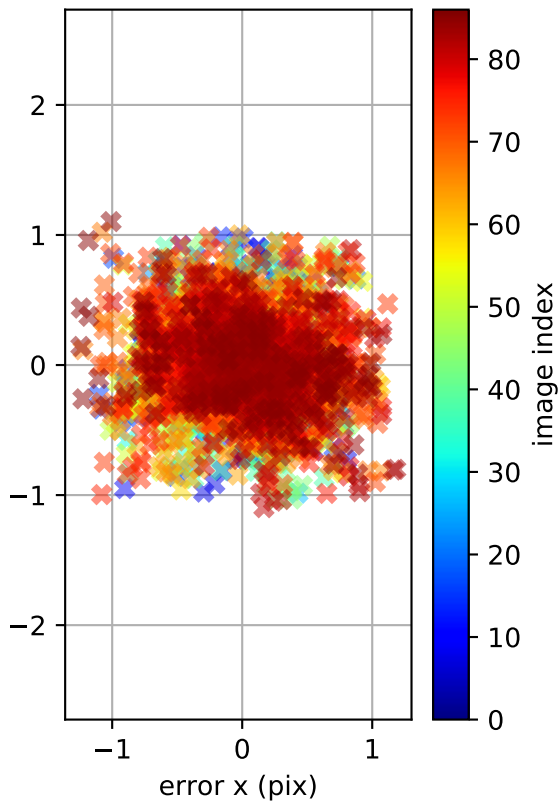
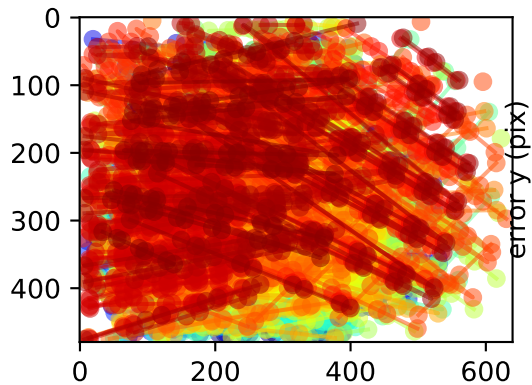
cam1: polar error



cam1: azimuthal error

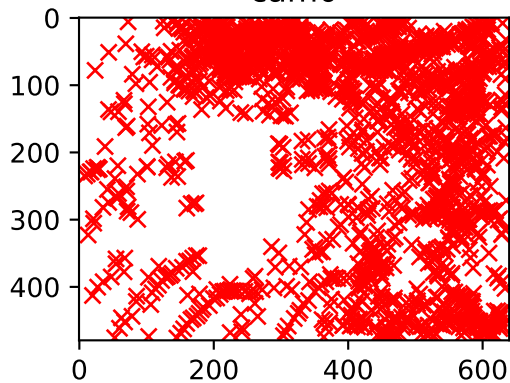


cam1: reprojection errors



Location of removed outlier corners

cam0



cam1

