

Calibration results

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Camera-system parameters:

cam0 (/t265/fisheye1/image_raw):

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

distortion: [-0.0087478 0.04669797 -0.04348087 0.00785929] +- [0.00414005 0.01229343 0.01341791 0.00491794]

projection: [285.24898789 285.99964868 426.51375763 404.97720118] +- [0.02430442 0.02453696 0.17433153 0.17553092]

reprojection error: [0.000021, 0.000001] +- [0.231047, 0.215231]

cam1 (/t265/fisheye2/image_raw):

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

distortion: [-0.01012828 0.05094139 -0.04827039 0.0097332] +- [0.00387629 0.01099837 0.01143883 0.00399167]

projection: [285.49992163 286.20780673 430.61379774 398.76253161] +- [0.02387105 0.02392968 0.17418077 0.16903509]

reprojection error: [-0.000017, 0.000000] +- [0.224091, 0.211024]

baseline T_1_0:

q: [0.00112021 0.00256065 -0.00073643 0.99999582] +- [0.00068802 0.00067645 0.00010662]

t: [-0.06462599 -0.00027747 -0.00021815] +- [0.00011729 0.00011189 0.00022165]

Target configuration

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Type: aprilgrid

Tags:

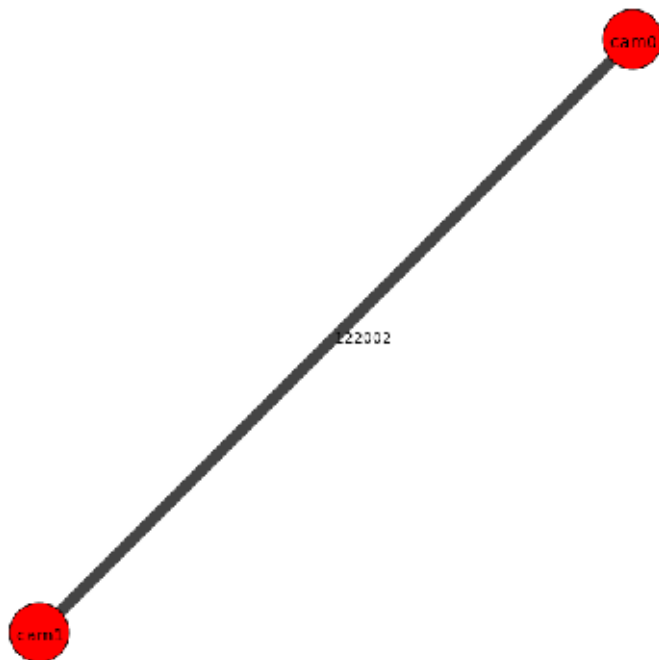
Rows: 6

Cols: 6

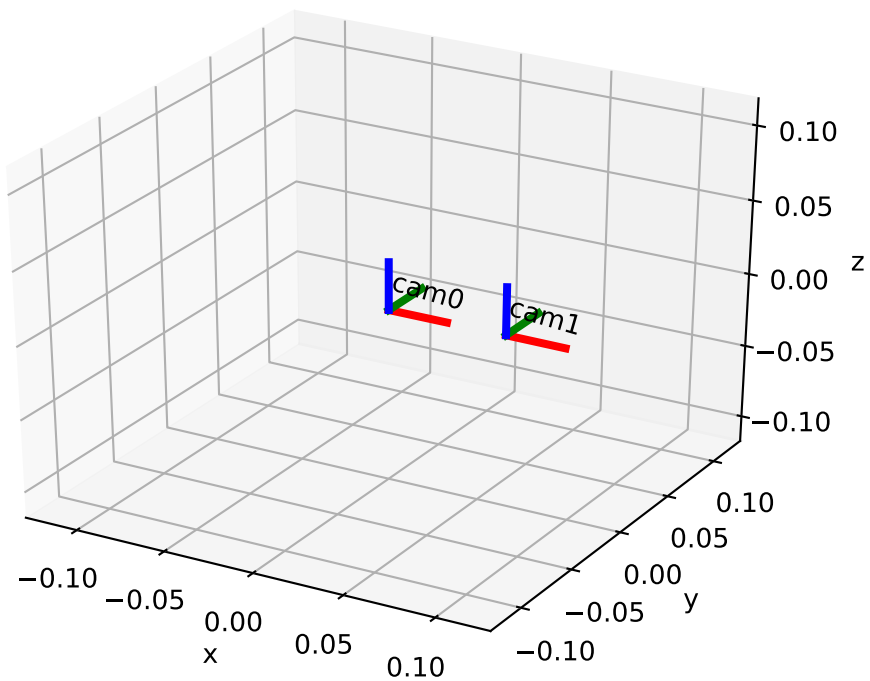
Size: 0.088 [m]

Spacing 0.026399999999999996 [m]

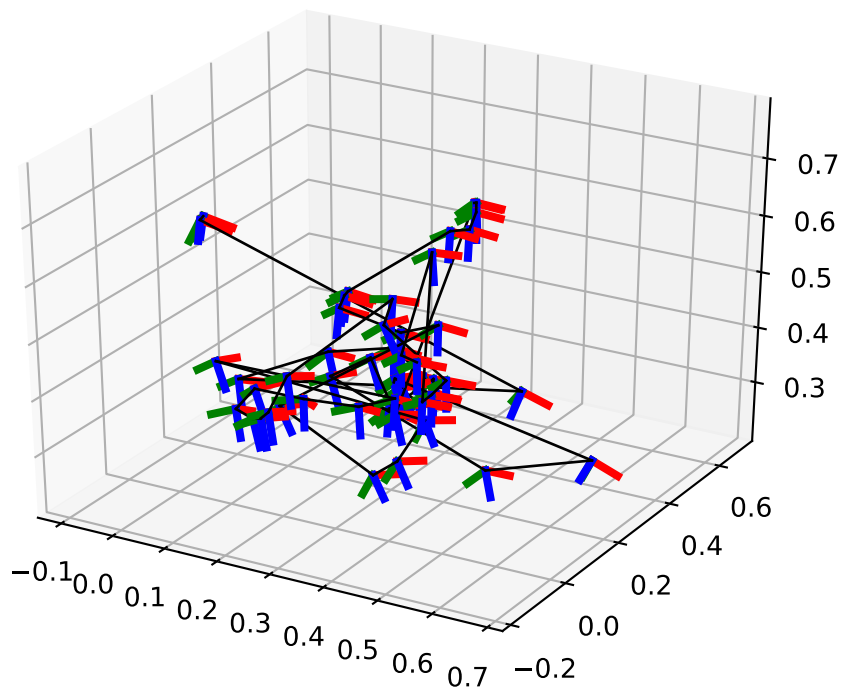
Inter-camera observations graph (edge weight=#mutual obs.)



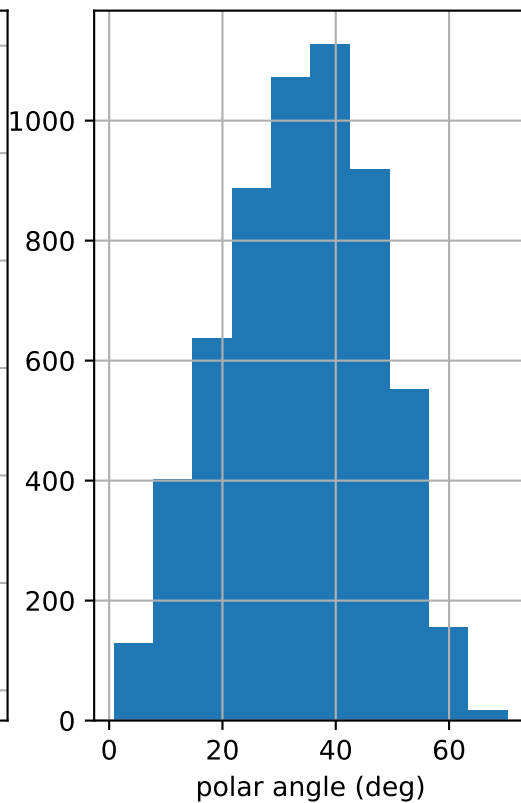
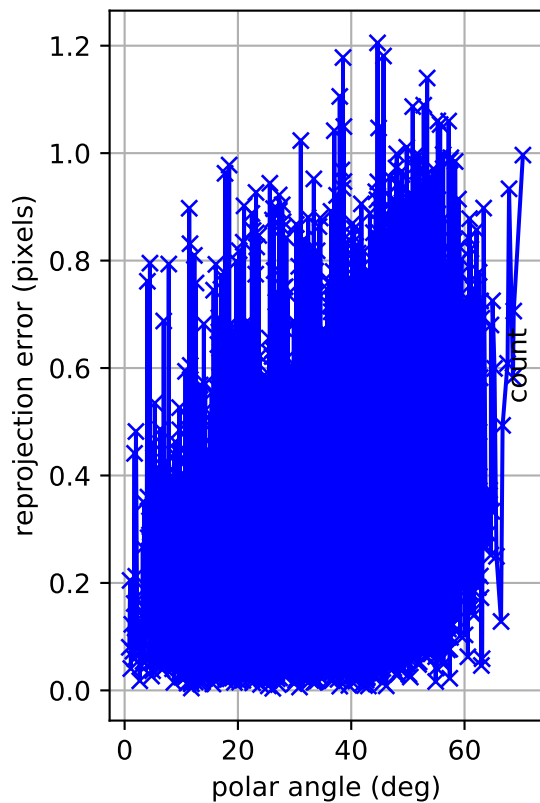
camera system



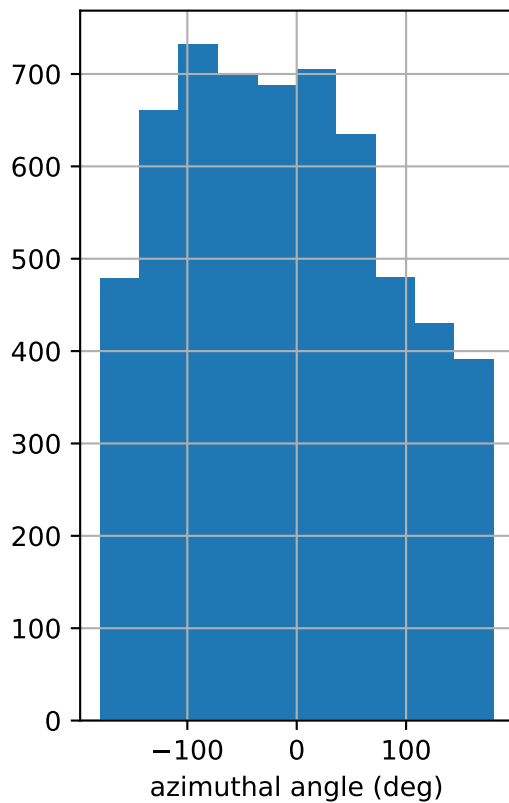
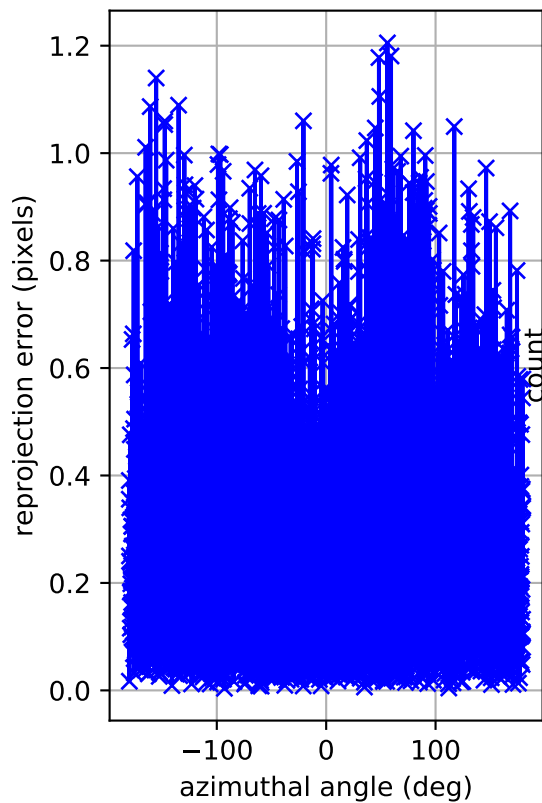
cam0: estimated poses



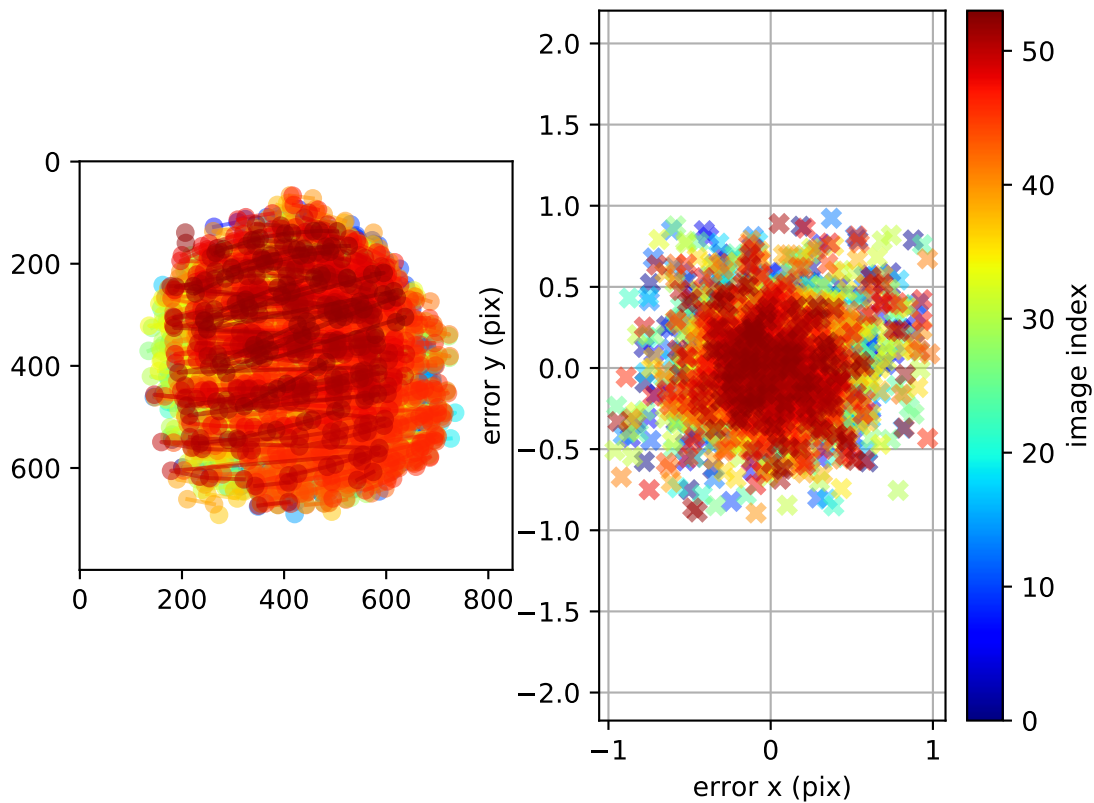
cam0: polar error



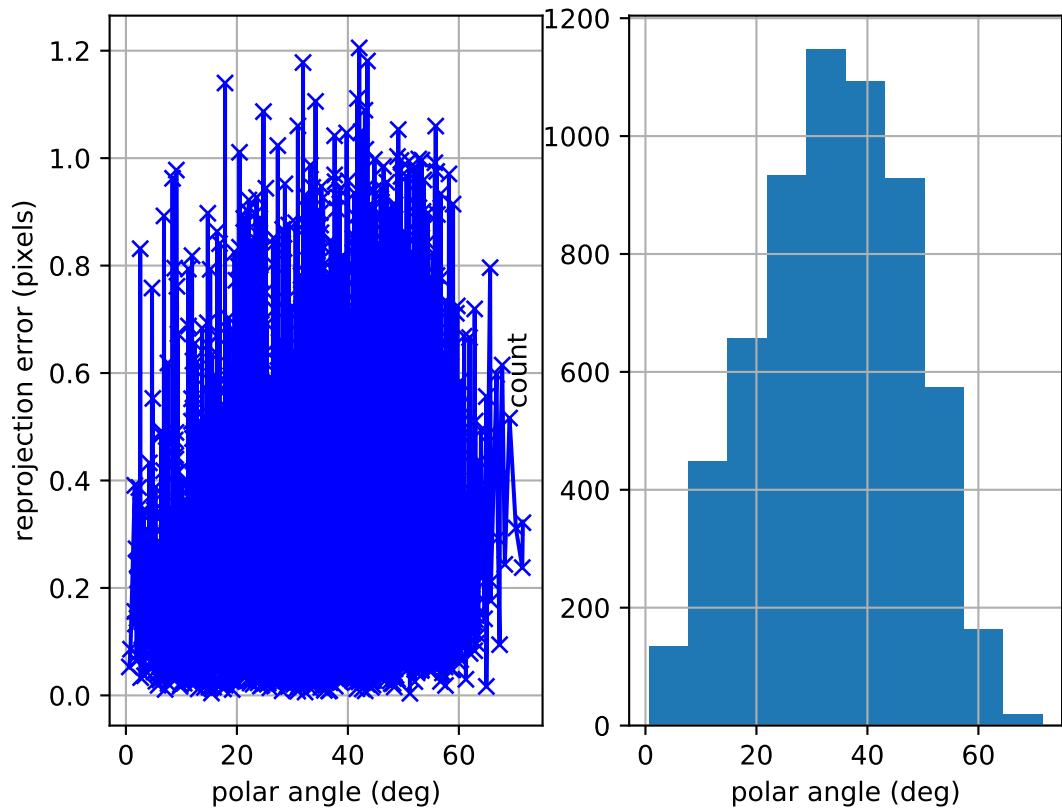
cam0: azimuthal error



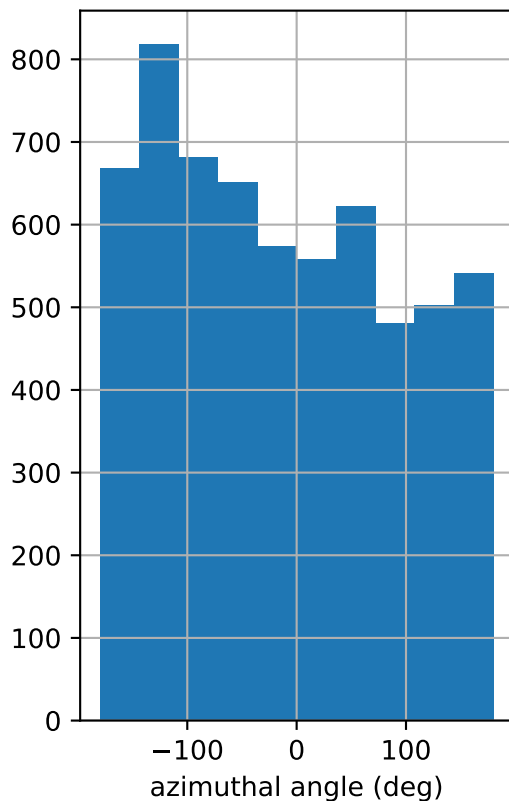
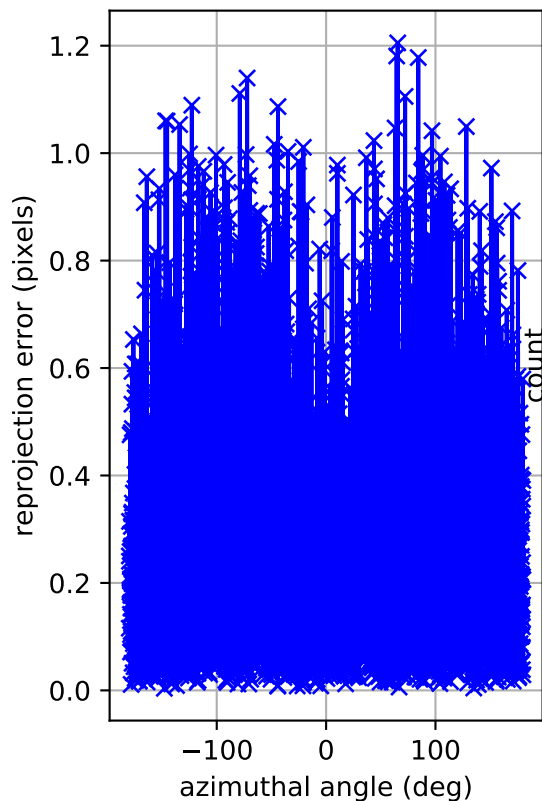
cam0: reprojection errors



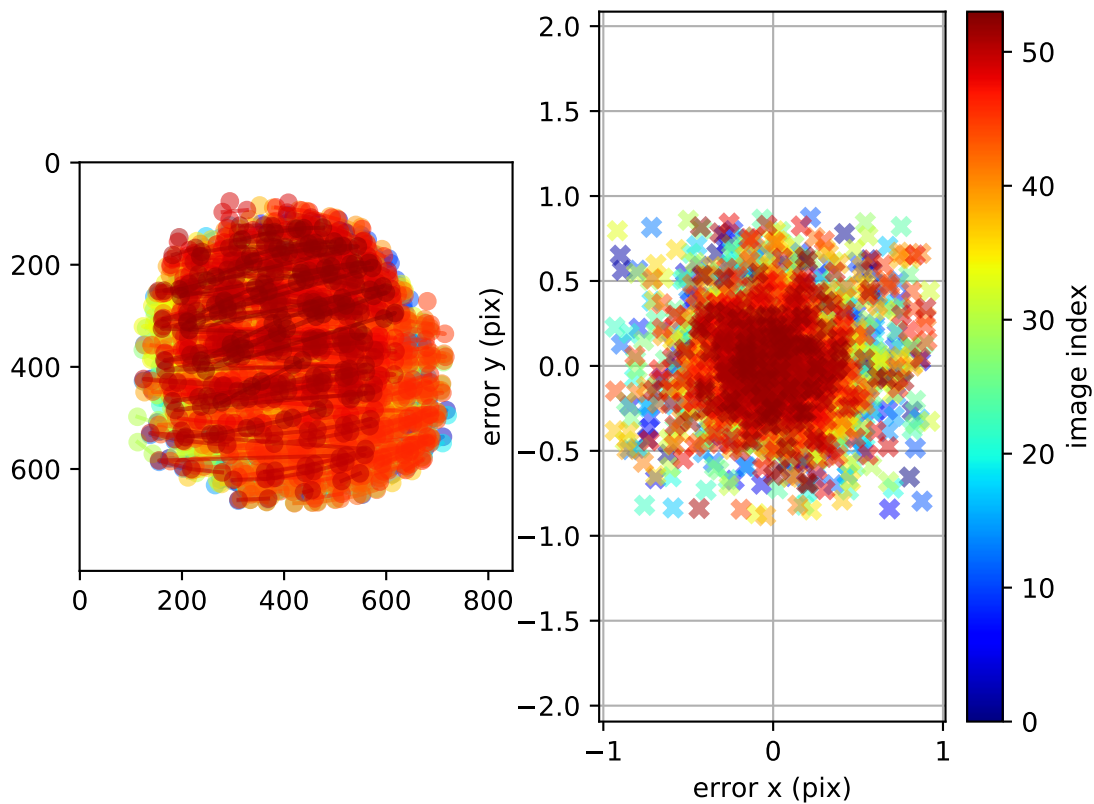
cam1: polar error



cam1: azimuthal error

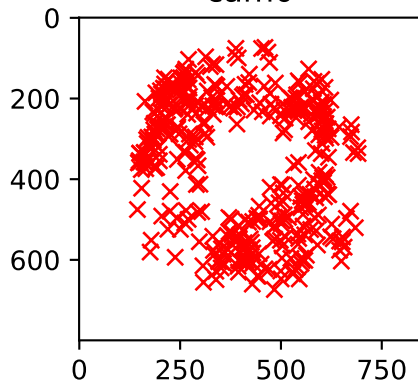


cam1: reprojection errors



Location of removed outlier corners

cam0



cam1

