

Calibration results

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Camera-system parameters:

cam0 (/left/camera/image_raw):

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

distortion: [-0.37079601 0.11937875 0.00202416 -0.00287506] +- [0.00216315 0.00808033 0.00008547 0.00019933]

projection: [3128.22314812 3127.05561249 1230.36094426 1055.97922963] +- [0.6113351 0.59750847 0.03734507 1.36094583]

reprojection error: [0.000025, -0.000061] +- [1.426340, 1.803504]

cam1 (/right/camera/image_raw):

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

distortion: [-0.37636477 0.15533051 0.00127093 -0.000817] +- [0.00267504 0.01917719 0.00010695 0.00010736]

projection: [3118.52167212 3126.10171744 1280.19592377 1016.25264308] +- [0.60306209 0.60715683 0.04790917 1.15912043]

reprojection error: [-0.000028, -0.000060] +- [1.154479, 1.285452]

cam2 (/mapir/image_raw):

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

distortion: [-0.03604069 -0.4257777 0.00085291 0.00169791] +- [0.00991895 0.07430494 0.00033385 0.0003801]

projection: [1069.51000051 1074.48913261 281.24444875 218.62354489] +- [0.97052809 0.99088017 0.02283727 0.18385689]

reprojection error: [0.000182, -0.000957] +- [4.035250, 5.281321]

baseline T_1_0:

q: [-0.00334271 0.00164897 -0.02049711 0.99978296] +- [0.00079742 0.00007703 0.00004345]

t: [-0.12016498 -0.00330067 0.00040638] +- [0.00005133 0.00004422 0.00028963]

baseline T_2_1:

q: [0.00590505 0.00227599 0.00556093 0.99996451] +- [0.00024859 0.00017471 0.00011032]

t: [0.08261999 0.01179713 -0.01302372] +- [0.00013055 0.00012194 0.00075259]

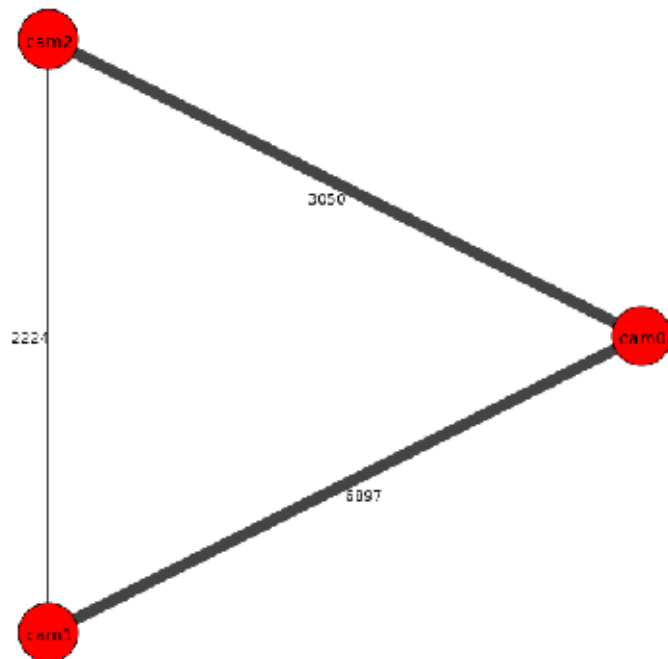
Target configuration

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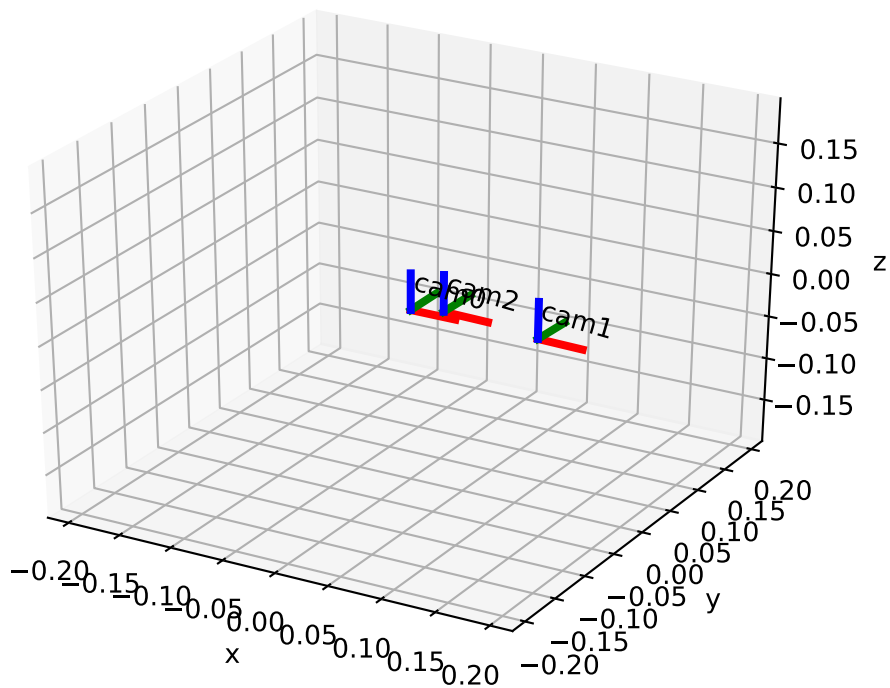
Type: aprilgrid

Tags:
Rows: 6
Cols: 6
Size: 0.032 [m]
Spacing 0.01 [m]

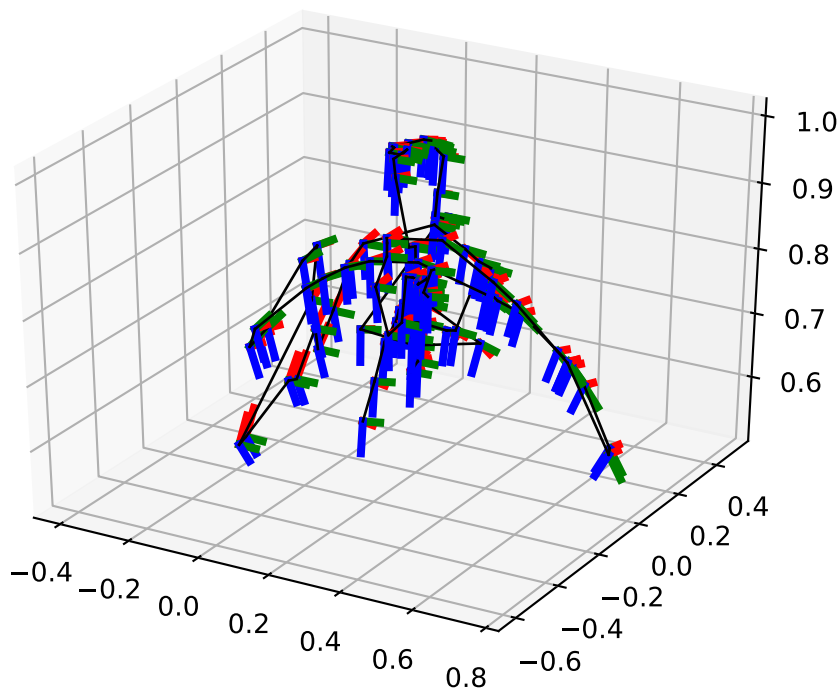
Inter-camera observations graph (edge weight=#mutual obs.)



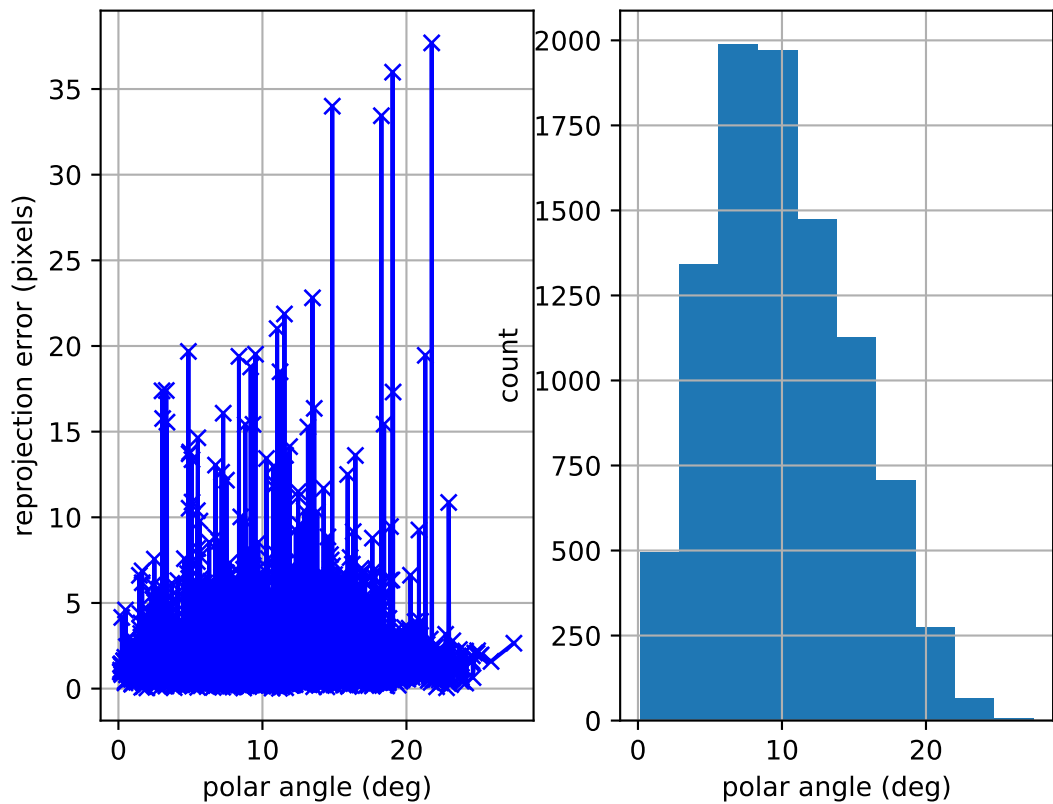
camera system



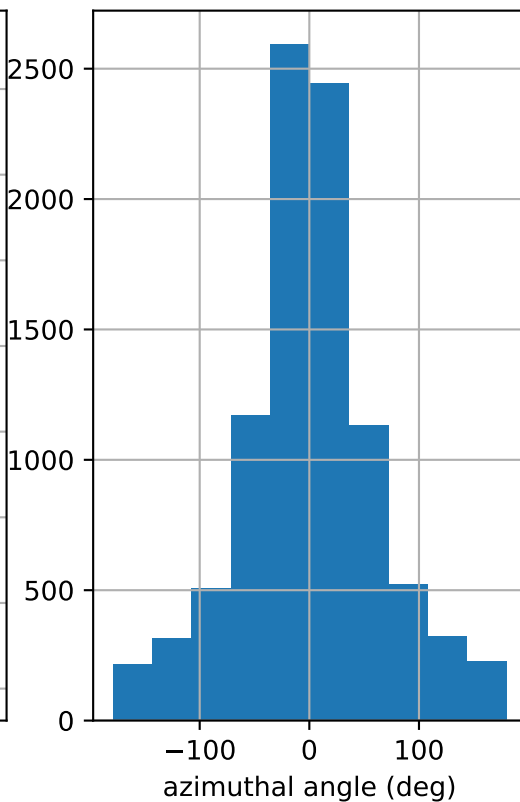
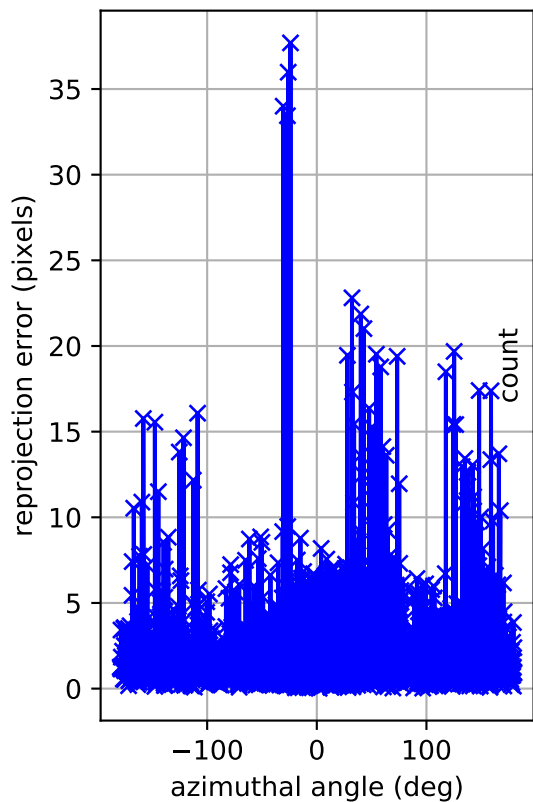
cam0: estimated poses



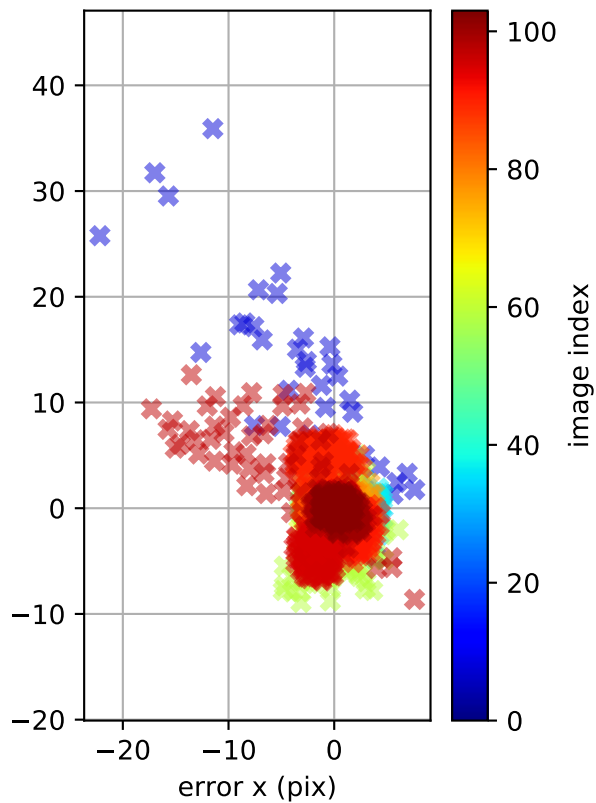
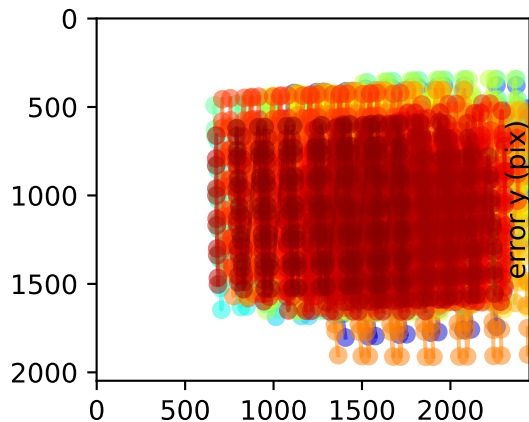
cam0: polar error



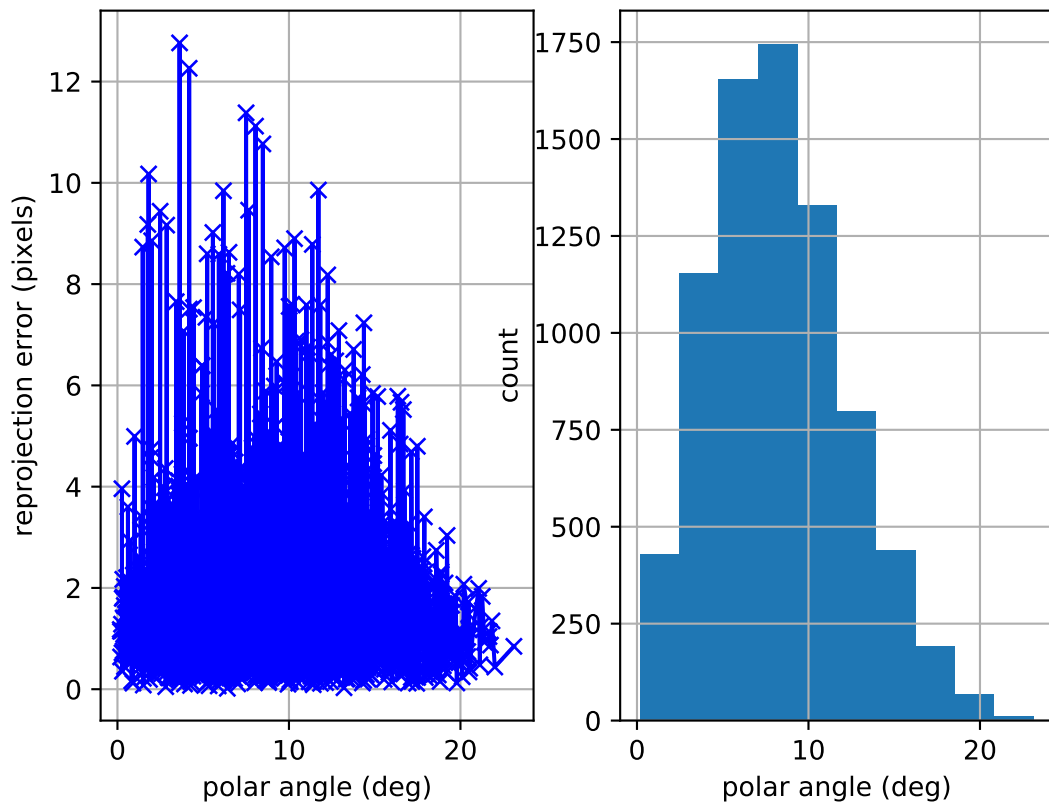
cam0: azimuthal error



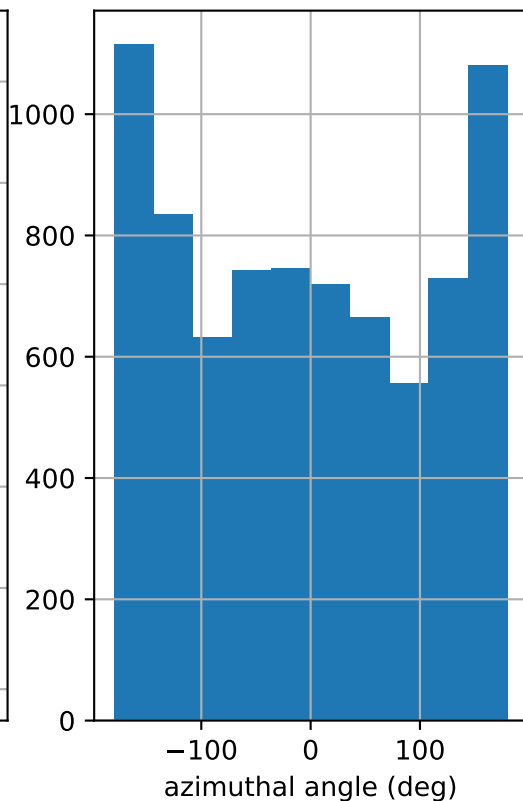
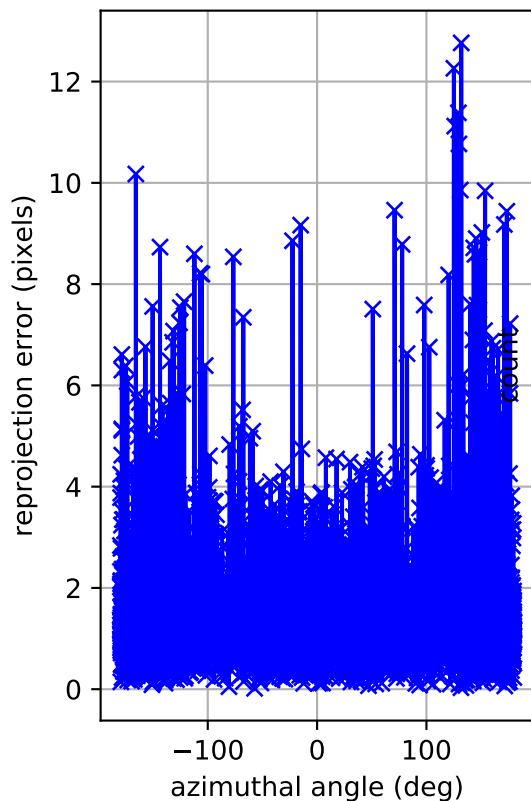
cam0: reprojection errors



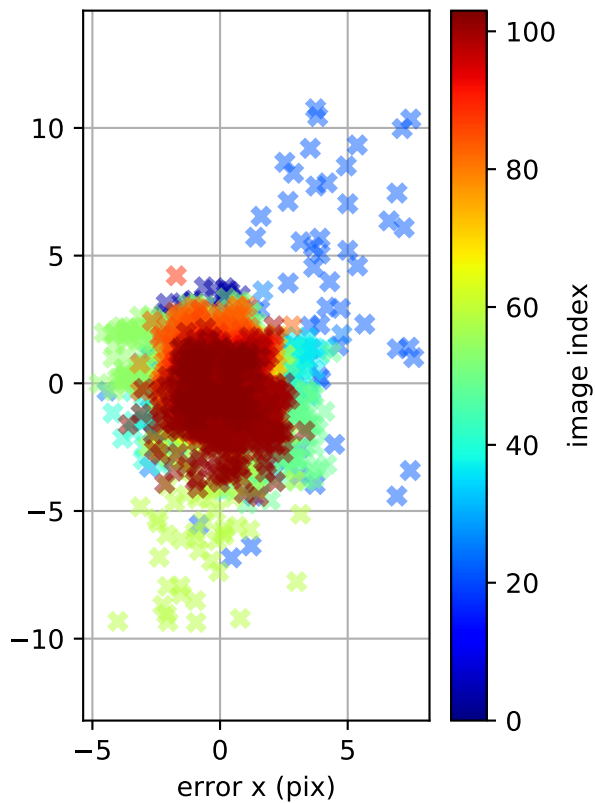
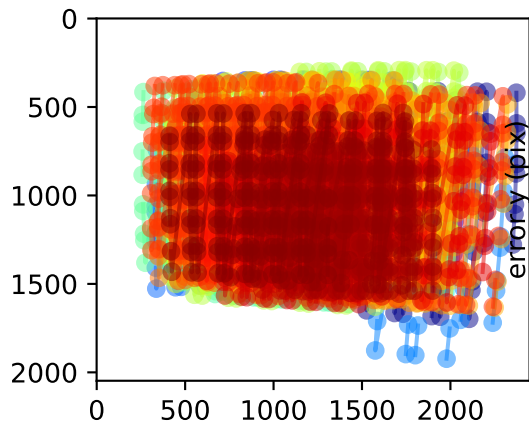
cam1: polar error



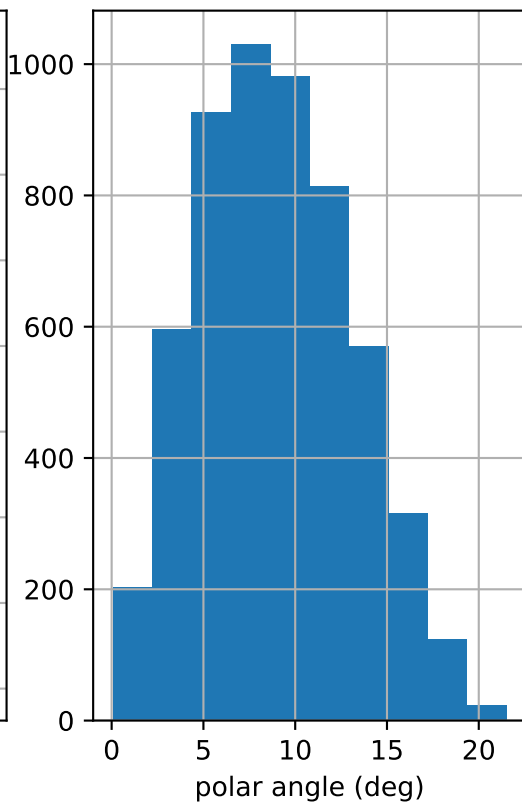
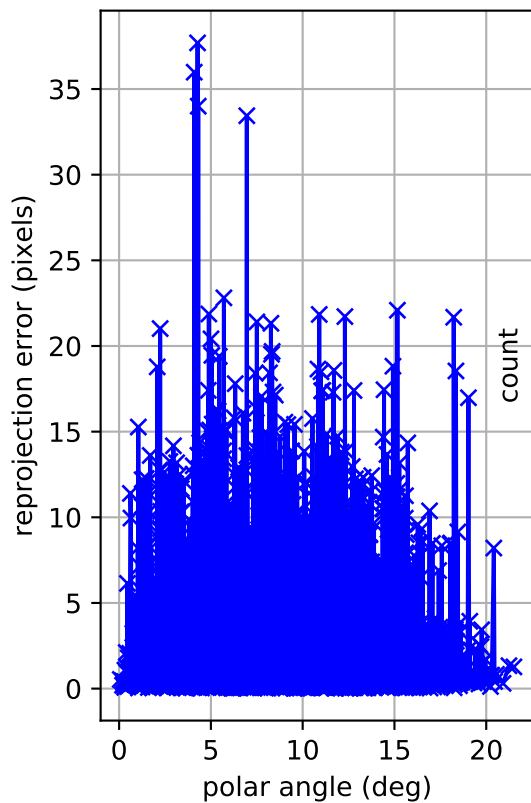
cam1: azimuthal error



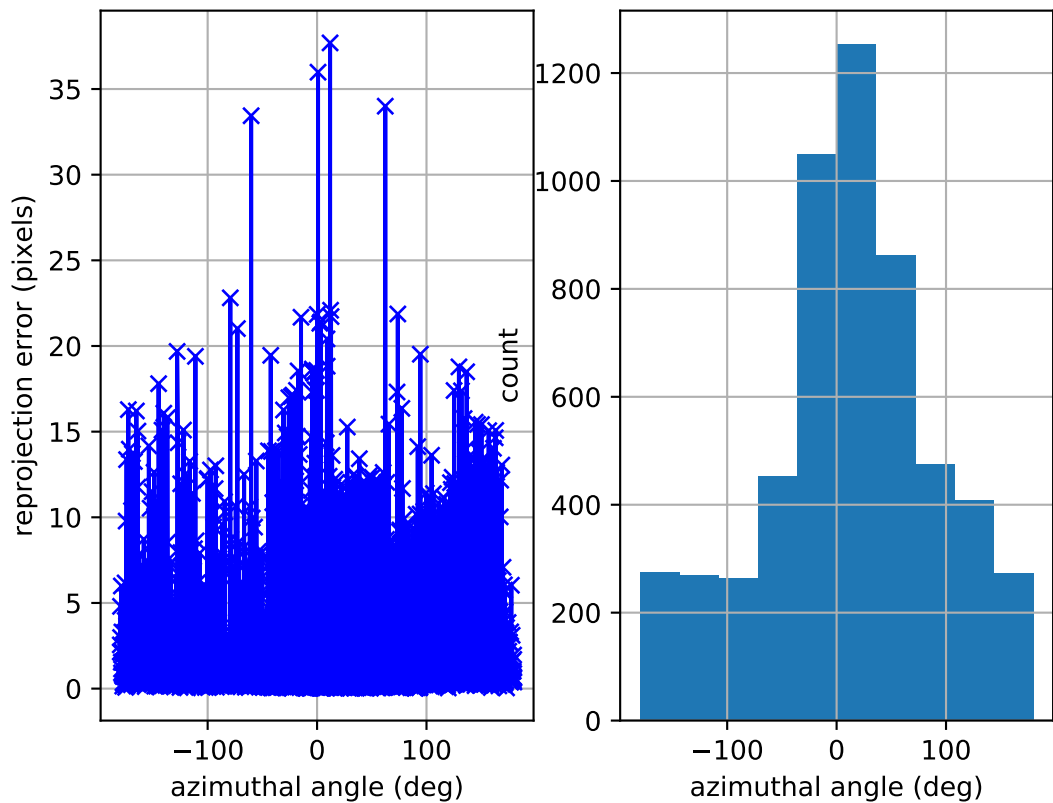
cam1: reprojection errors



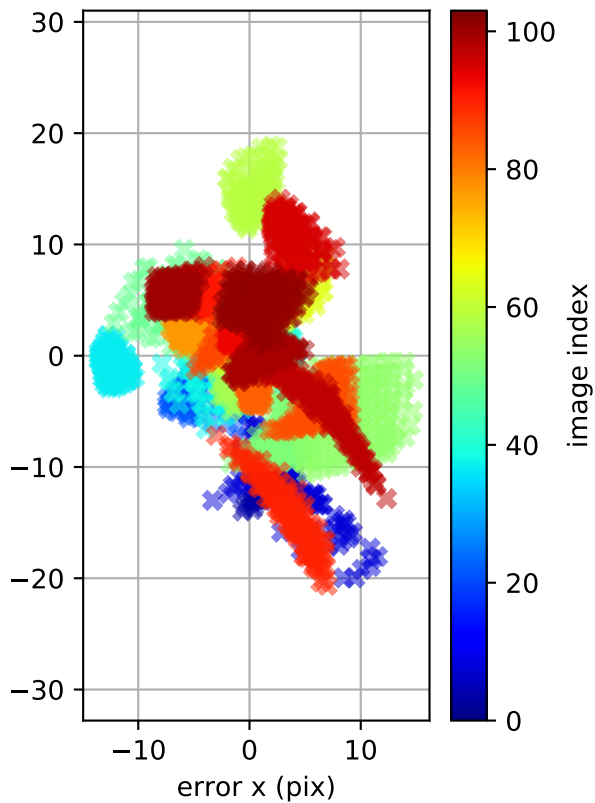
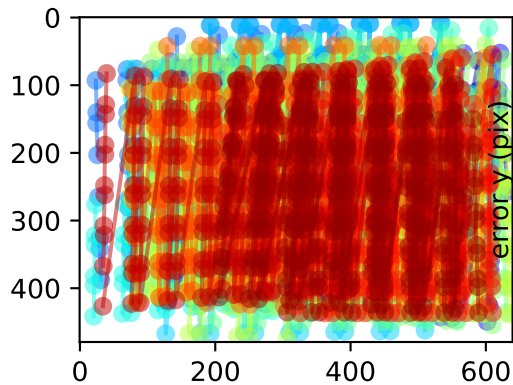
cam2: polar error



cam2: azimuthal error

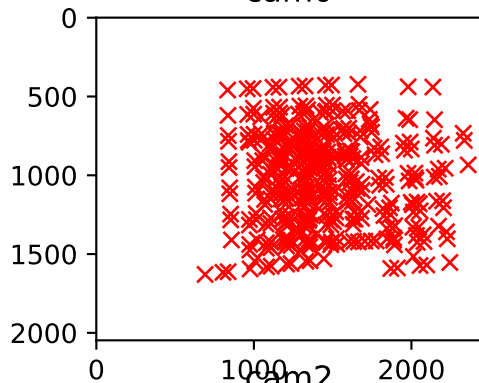


cam2: reprojection errors

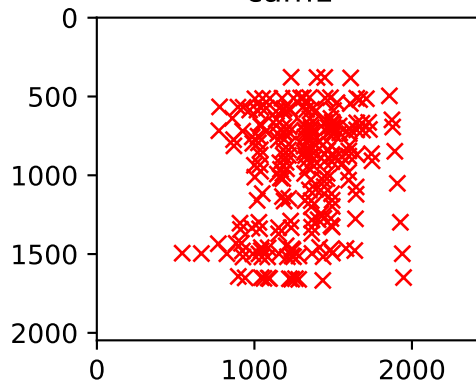


Location of removed outlier corners

cam0



cam1



cam2

