

Calibration results

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Camera-system parameters:

cam0 (/camera/infra1/image_rect_raw):

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

distortion: [-0.00621688 -0.00896583 -0.00669976 0.00472233] +- [0.0115626 0.0540737 0.00081699 0.00048464]

projection: [385.96635795 386.66632586 326.31560591 228.94820857] +- [0.14744279 0.11811894 0.19933403 0.74903573]

reprojection error: [-0.000053, -0.000038] +- [0.406923, 0.354979]

cam1 (/camera/infra2/image_rect_raw):

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

distortion: [0.00089123 -0.04974487 -0.00360597 0.00287944] +- [0.00827817 0.02584856 0.00074619 0.00059749]

projection: [386.50921164 386.61379526 324.94248128 231.01404188] +- [0.07926057 0.07360013 0.1079783 0.79087262]

reprojection error: [-0.000015, -0.000054] +- [0.357974, 0.358946]

cam2 (/camera/color/image_raw):

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

distortion: [0.09577766 -0.17830329 -0.00534013 -0.00423675] +- [0.00668545 0.02388738 0.00051457 0.0004607]

projection: [596.4430482 595.38459626 319.89488711 224.0996205] +- [0.09691663 0.09351669 0.19437523 0.60250046]

reprojection error: [0.000130, -0.000147] +- [0.568457, 0.547813]

baseline T_1_0:

q: [-0.00226263 -0.00086414 0.00035963 0.999997] +- [0.00320122 0.00078015 0.00023724]

t: [-0.05061547 -0.00002674 -0.00078005] +- [0.00019276 0.00019187 0.00030825]

baseline T_2_1:

q: [0.00207895 -0.01093059 0.00015844 0.99993809] +- [0.0026288 0.00067634 0.00020628]

t: [0.06623035 -0.00024971 0.00173897] +- [0.00016873 0.00016274 0.00022597]

Target configuration

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Type: checkerboard

Rows

Count: 8

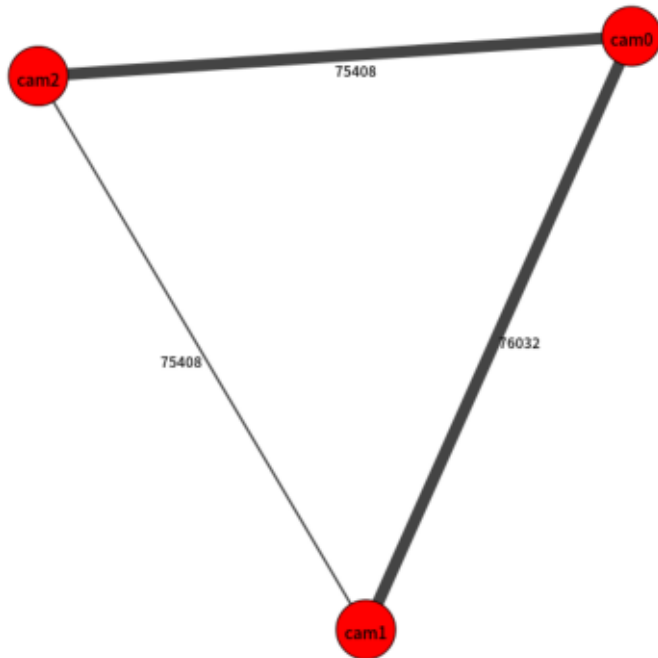
Distance: 0.0248 [m]

Cols

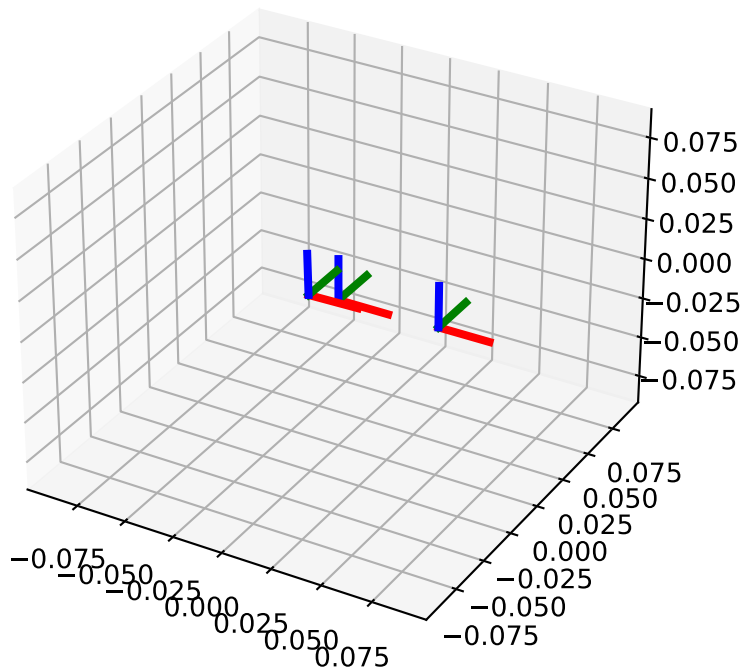
Count: 6

Distance: 0.0248 [m]

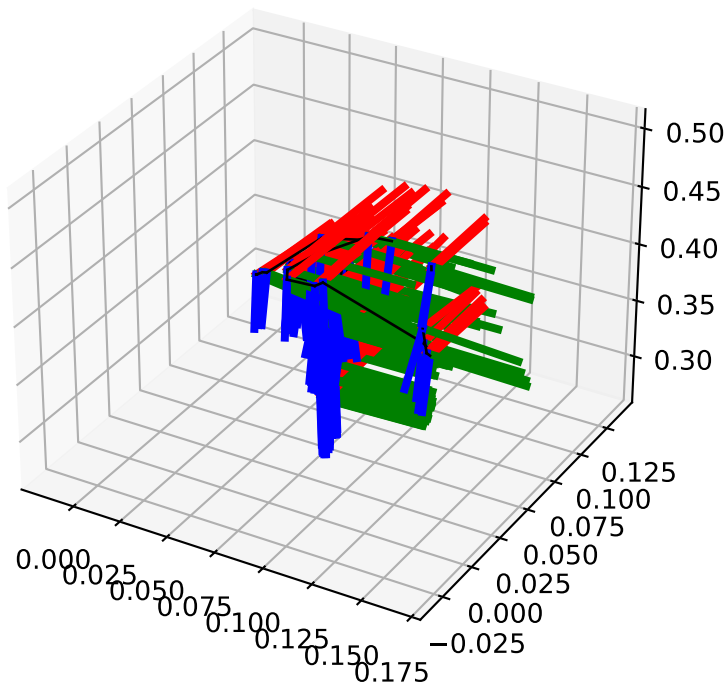
Inter-camera observations graph (edge weight=#mutual obs.)



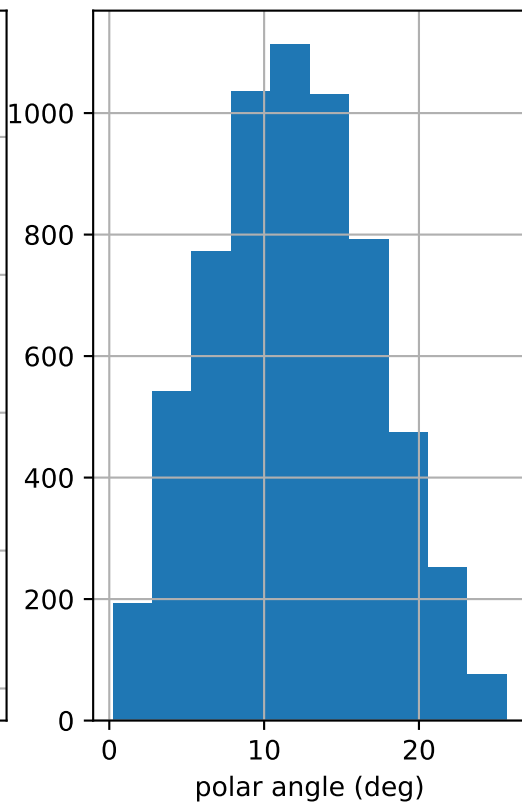
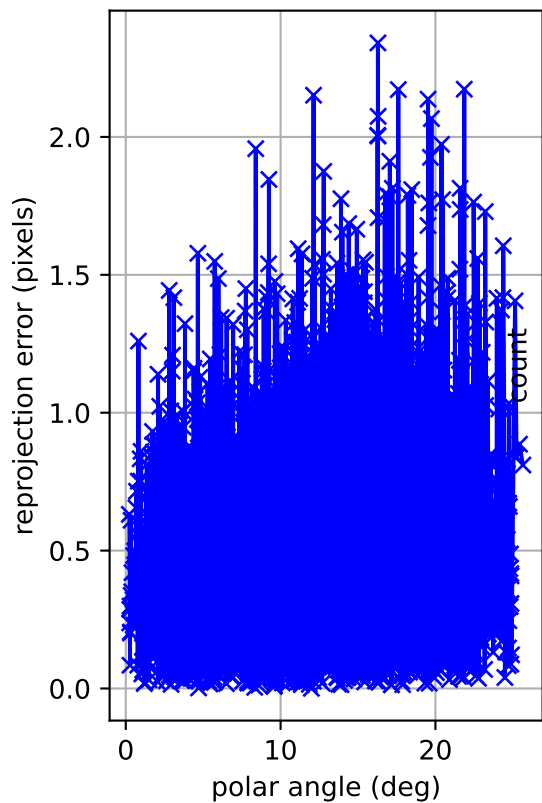
camera system



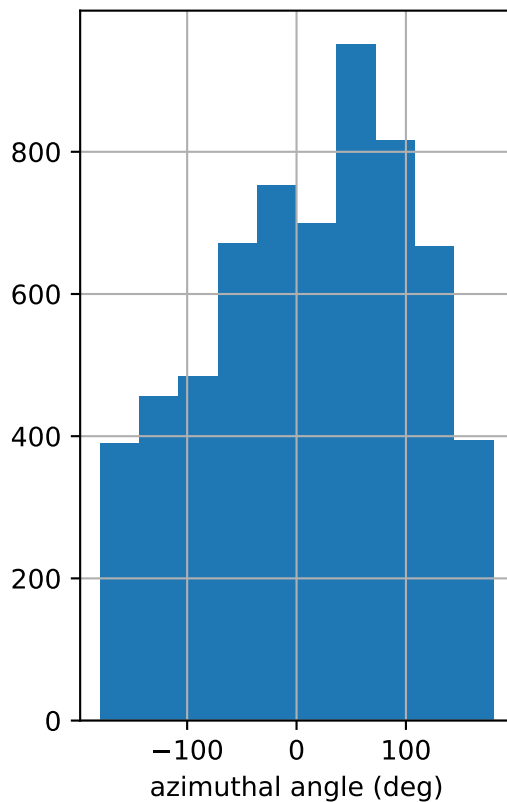
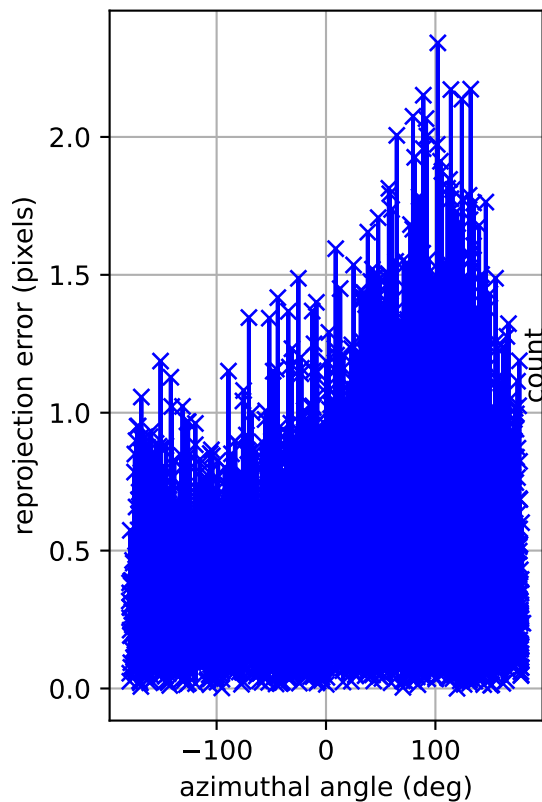
cam0: estimated poses



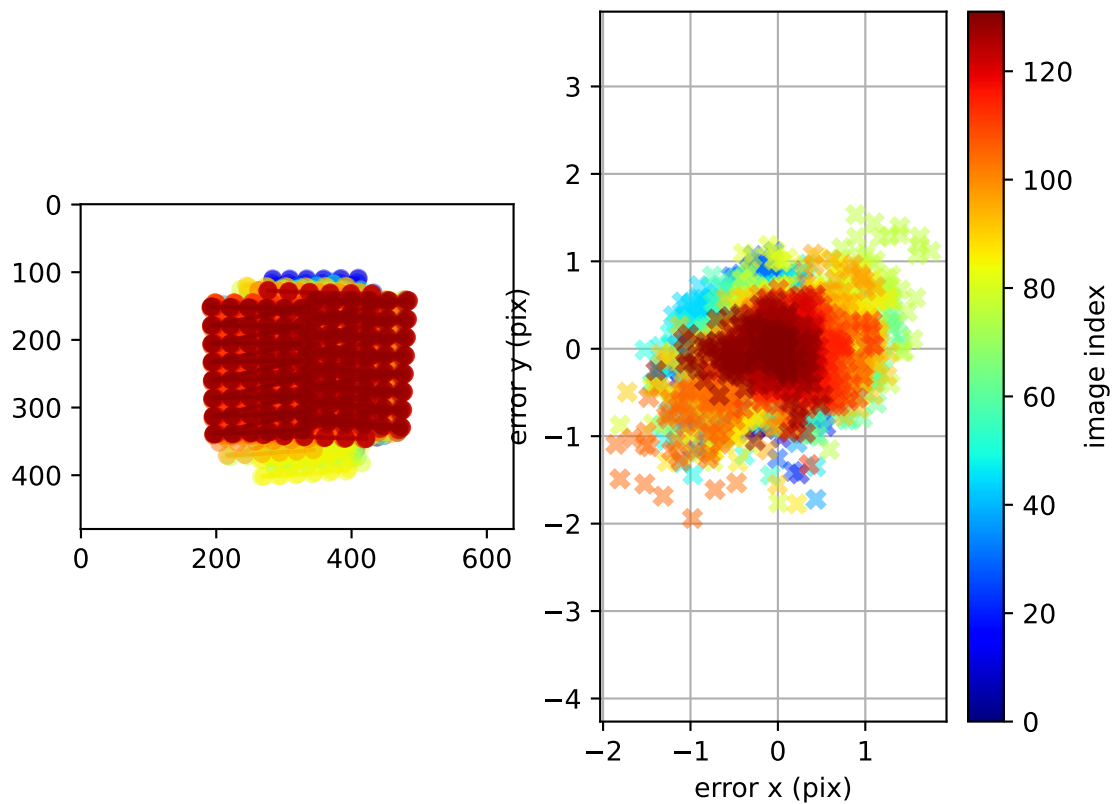
cam0: polar error



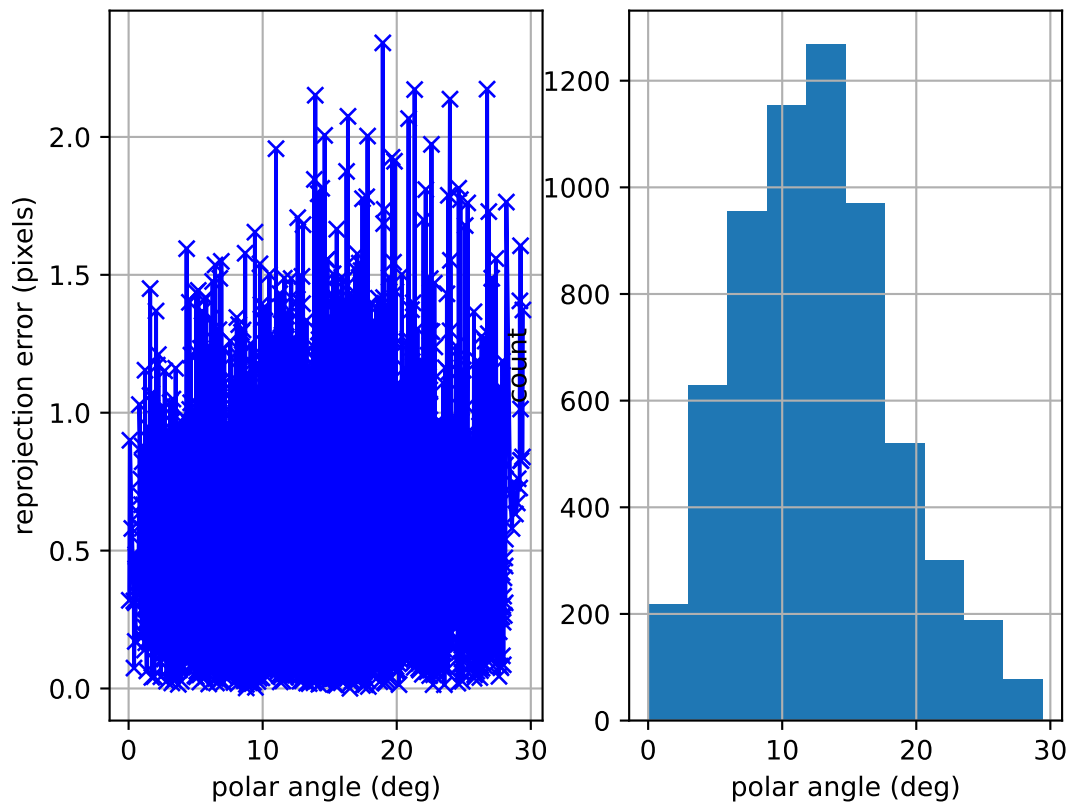
cam0: azimuthal error



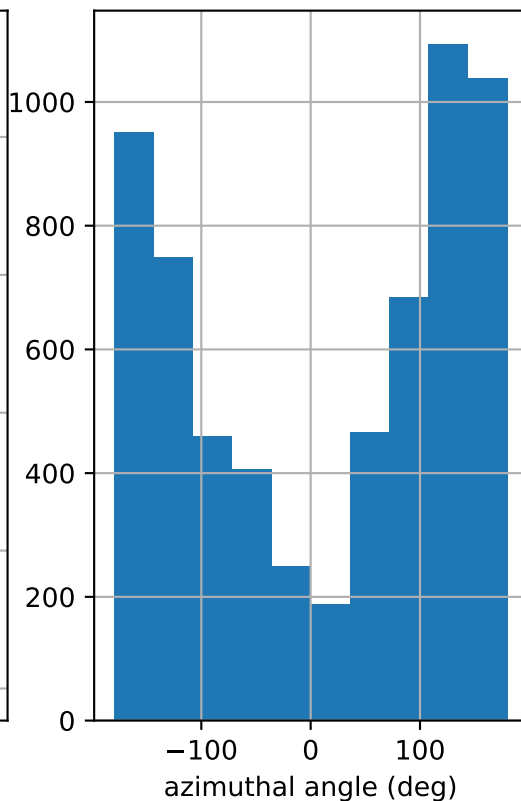
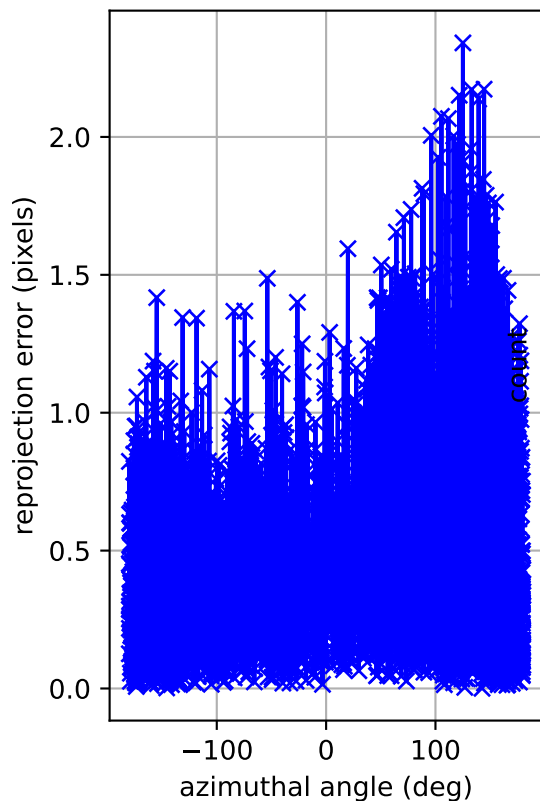
cam0: reprojection errors



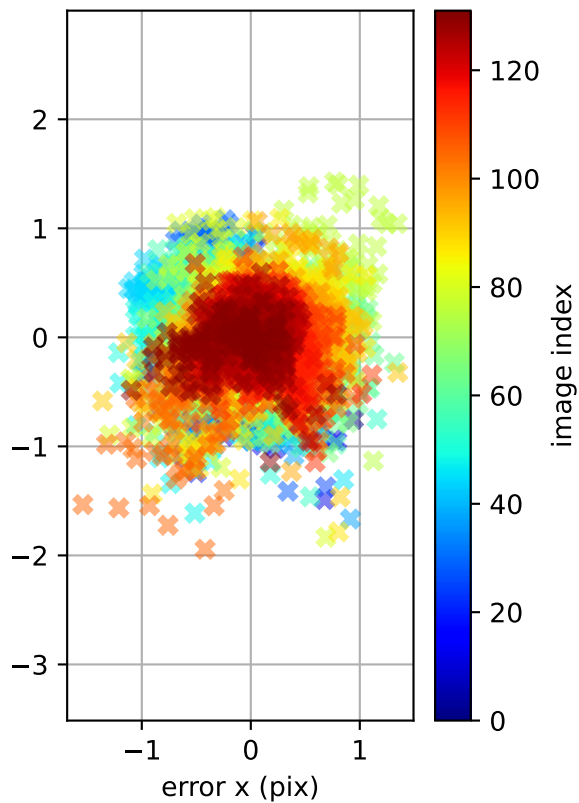
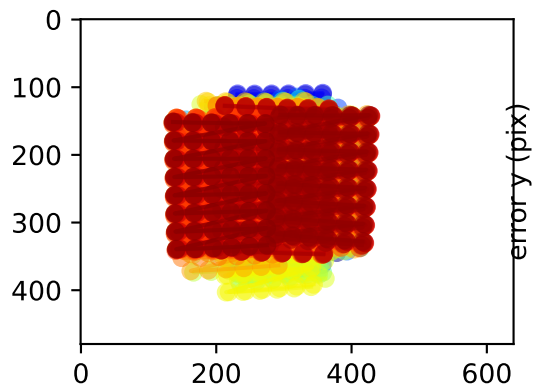
cam1: polar error



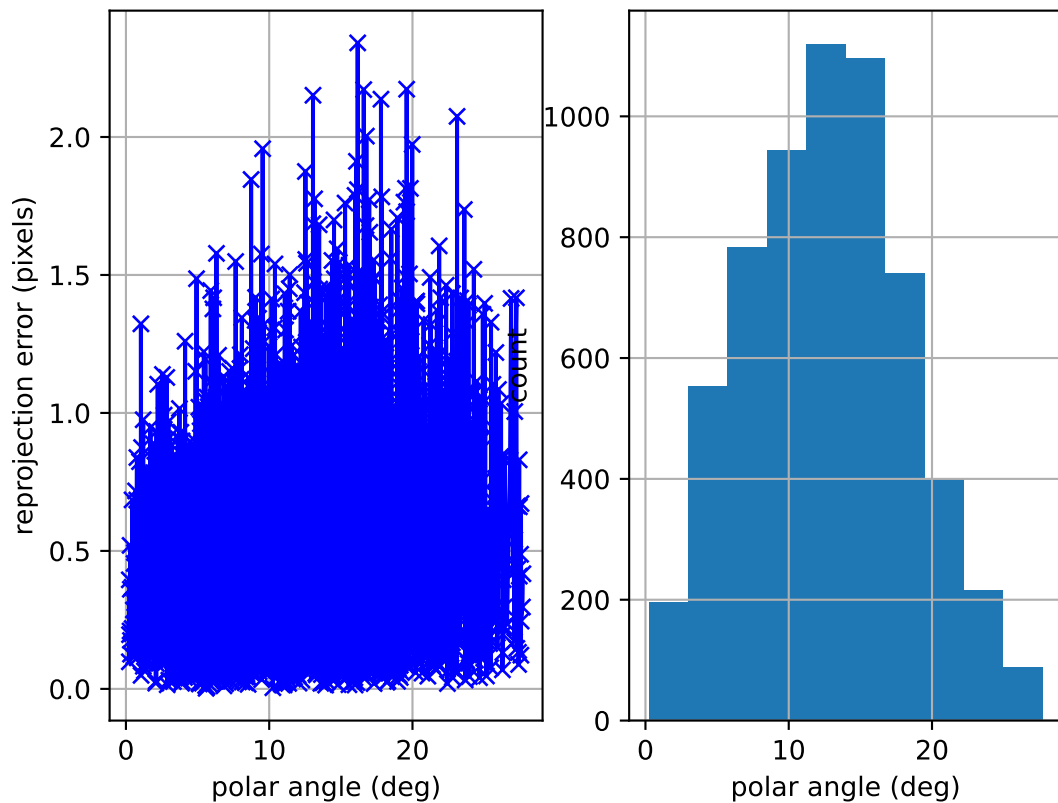
cam1: azimuthal error



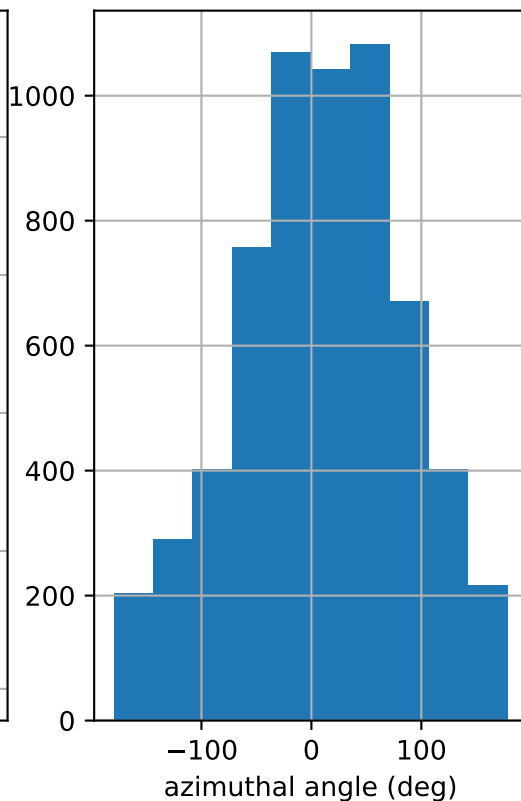
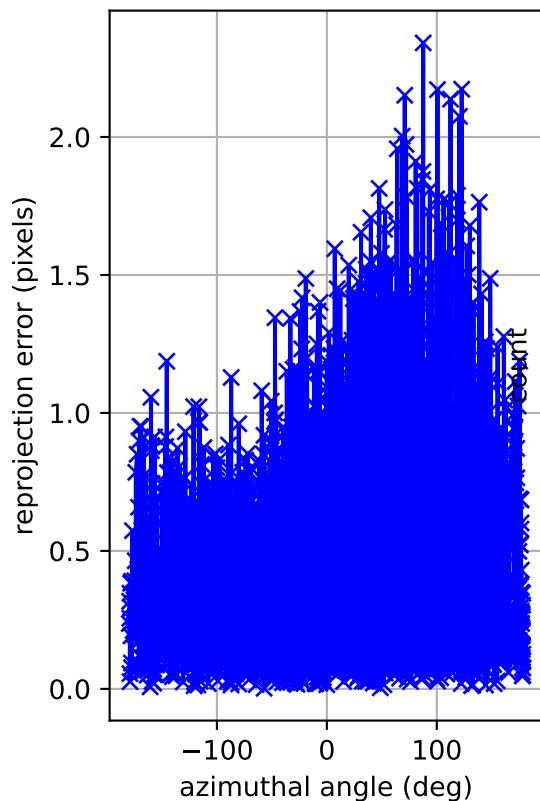
cam1: reprojection errors



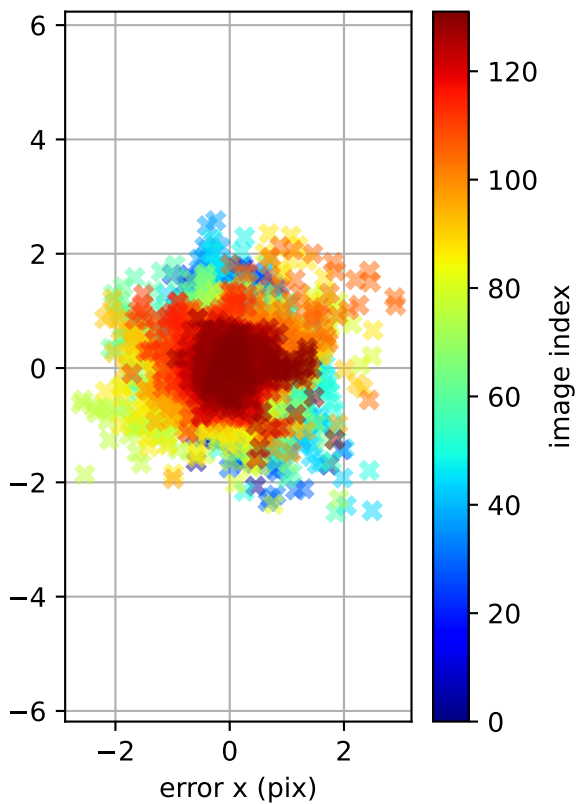
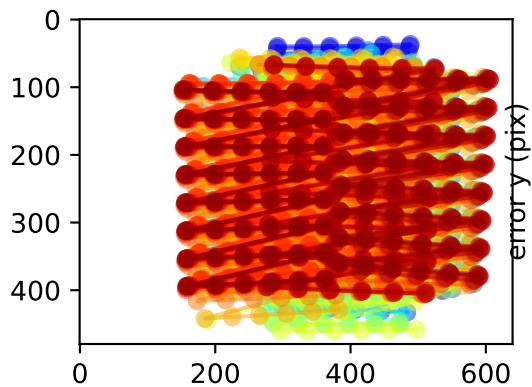
cam2: polar error



cam2: azimuthal error

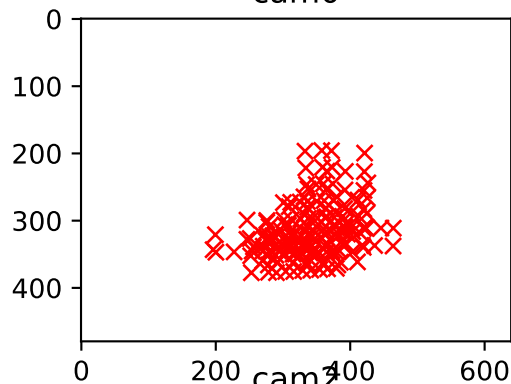


cam2: reprojection errors

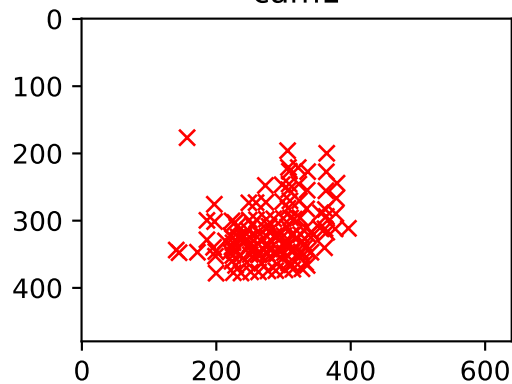


Location of removed outlier corners

cam0



cam1



cam2

