

Calibration results

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Camera-system parameters:

cam0 (/cam0/image_raw):

type: <class 'aslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [0.07536437 -0.18468836 0.00092726 0.00033364] +- [0.00560802 0.01507799 0.00053571 0.00044853]

projection: [1151.13341587 1150.30902036 648.80503297 365.50538407] +- [0.80018663 0.76459404 0.07637371 0.85366651]

reprojection error: [0.000121, -0.000036] +- [0.380177, 0.318709]

cam1 (/cam1/image_raw):

type: <class 'aslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [0.06143751 -0.13747218 0.00153052 -0.00356831] +- [0.00531193 0.01316079 0.00052539 0.00045102]

projection: [1155.11798085 1154.48430634 645.37252872 365.78508202] +- [0.80123604 0.76772923 0.14196111 0.82729782]

reprojection error: [-0.000098, -0.000042] +- [0.416945, 0.325086]

baseline T_1 0:

q: [-0.00087935 -0.00270995 -0.0008824 0.99999555] +- [0.00150475 0.00034032 0.00017118]

t: [-0.02997144 -0.00027389 0.00036353] +- [0.00010267 0.00006741 0.00030318]

Target configuration

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Type: aprilgrid

Tags:

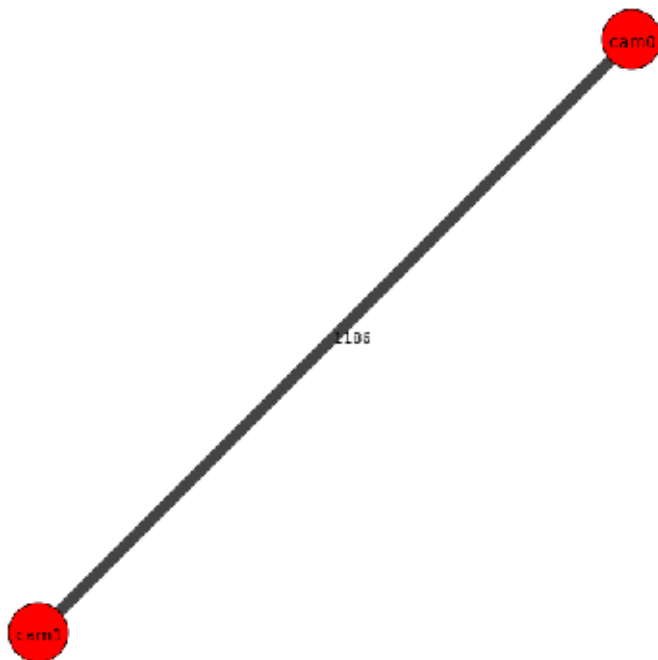
Rows: 4

Cols: 5

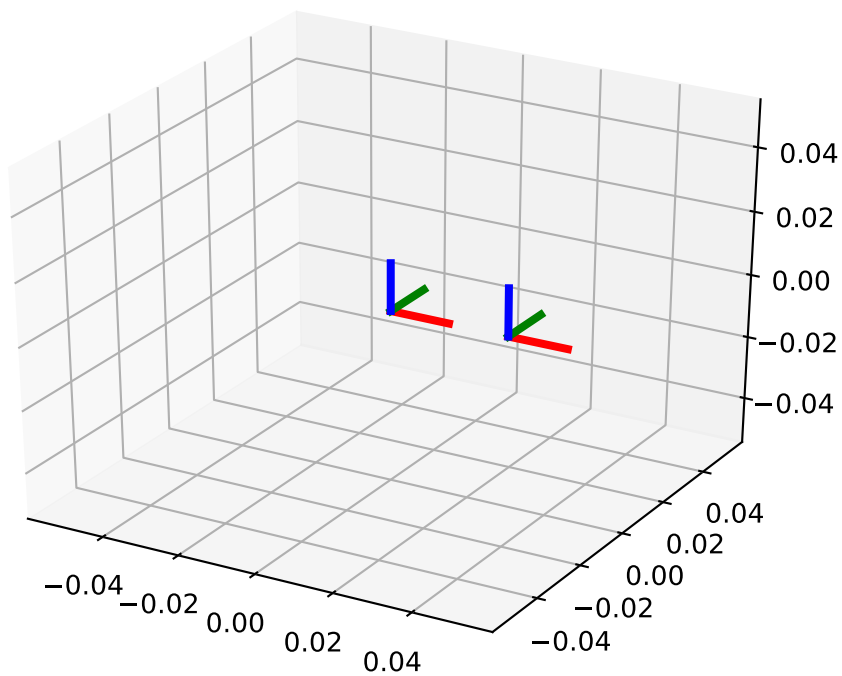
Size: 0.02 [m]

Spacing 0.004 [m]

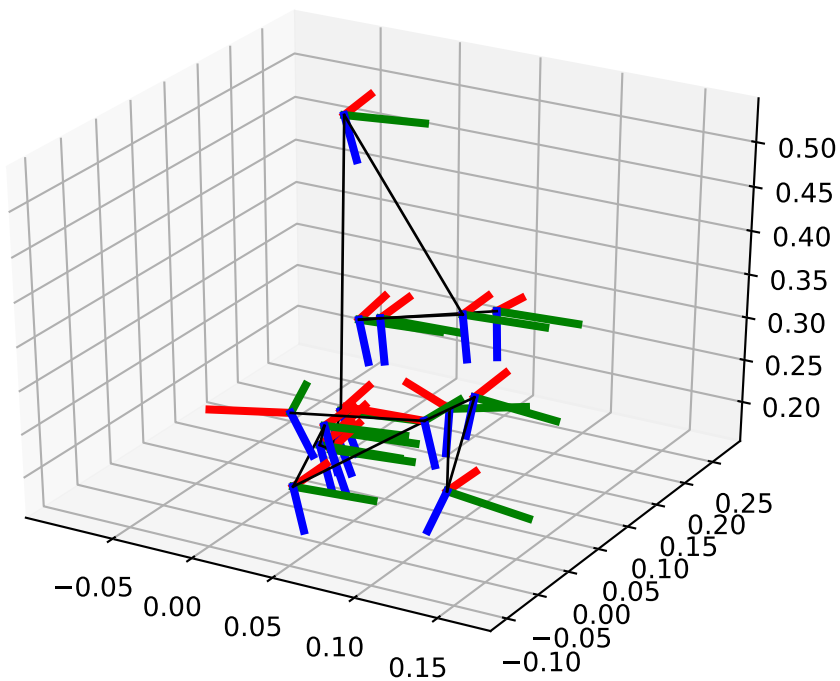
Inter-camera observations graph (edge weight=#mutual obs.)



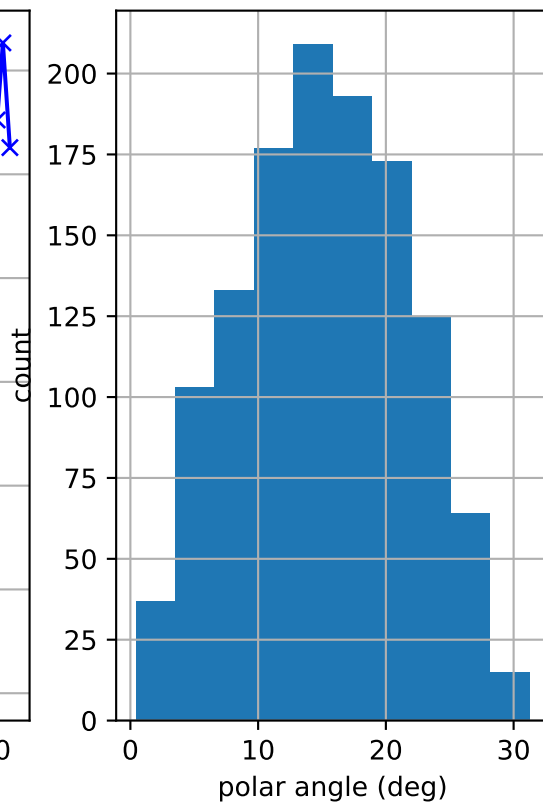
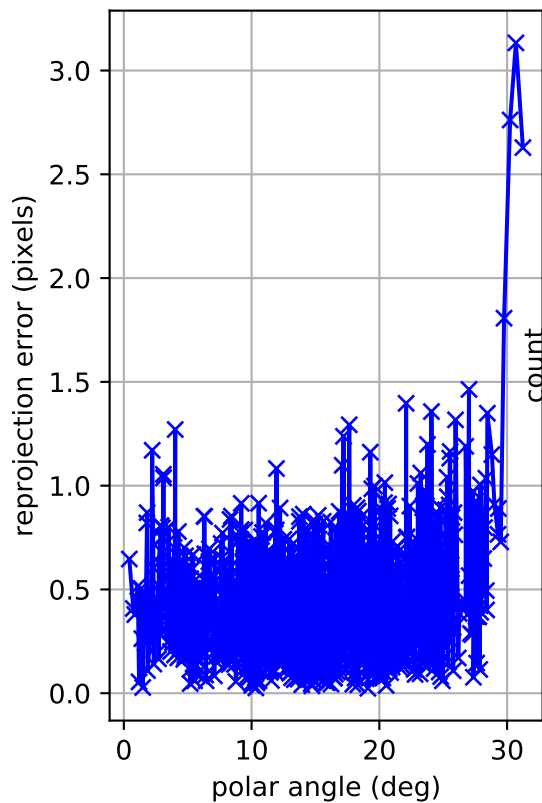
camera system



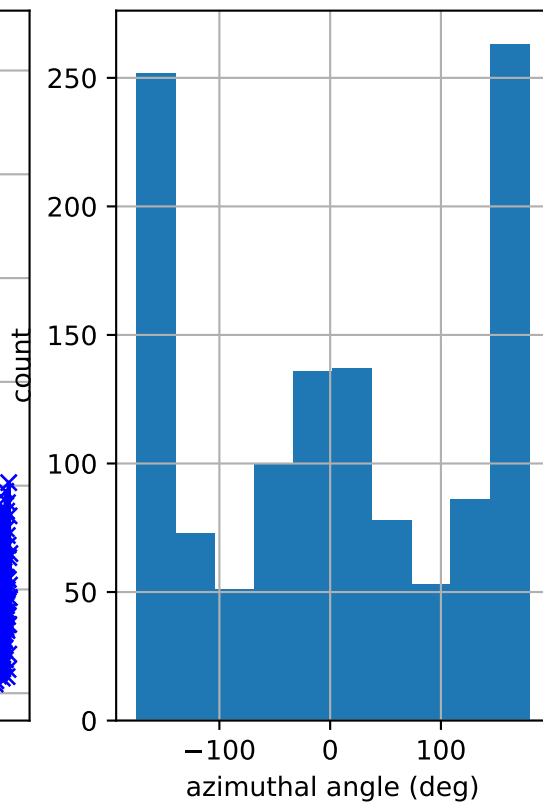
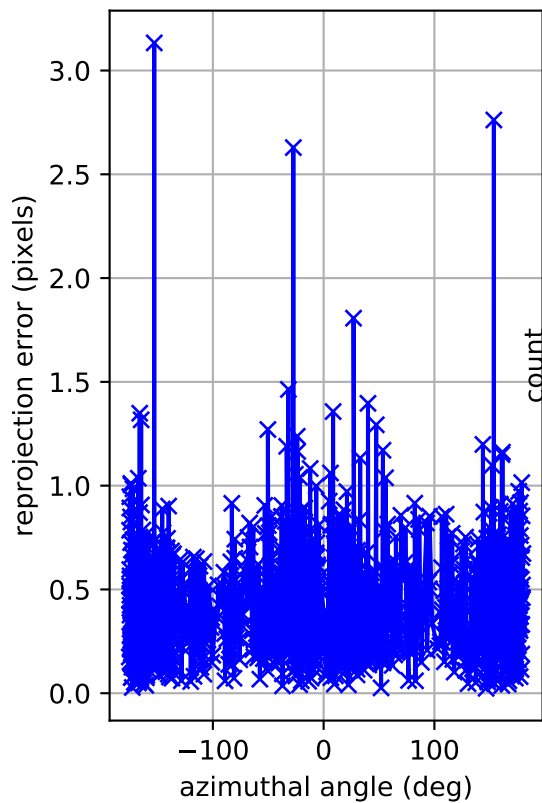
cam0: estimated poses



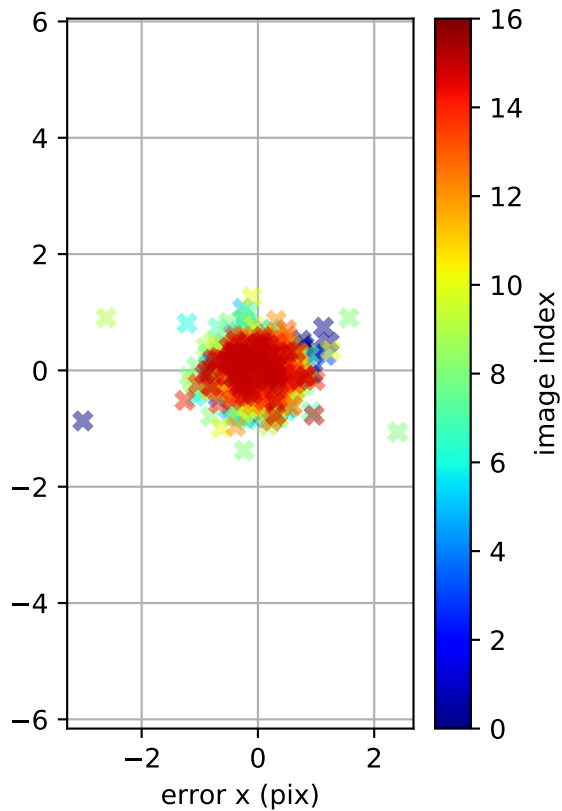
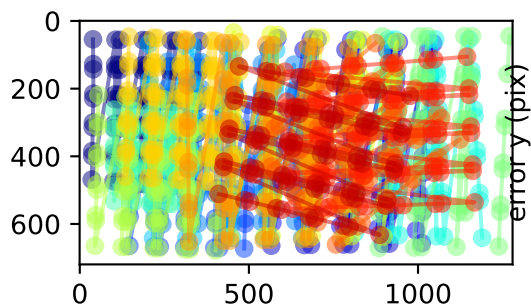
cam0: polar error



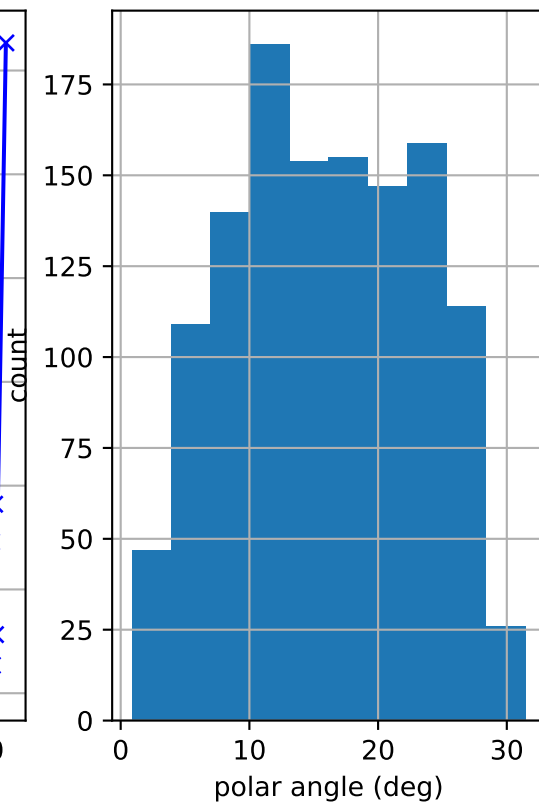
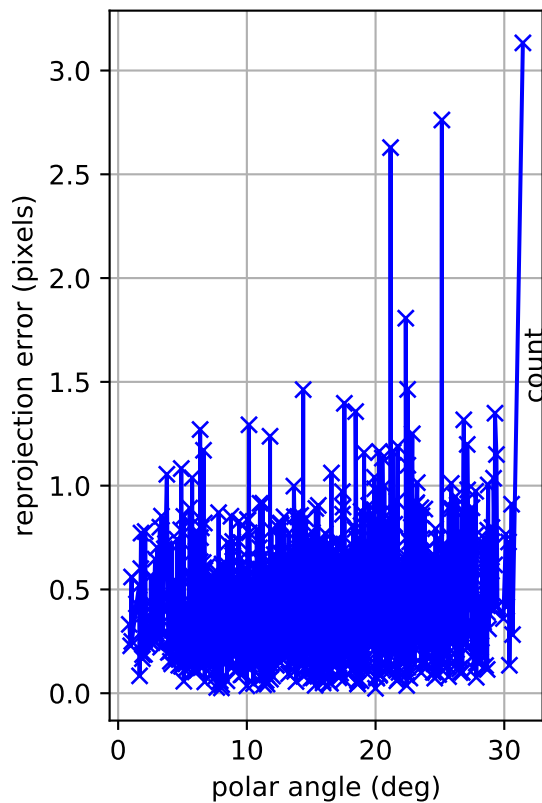
cam0: azimuthal error



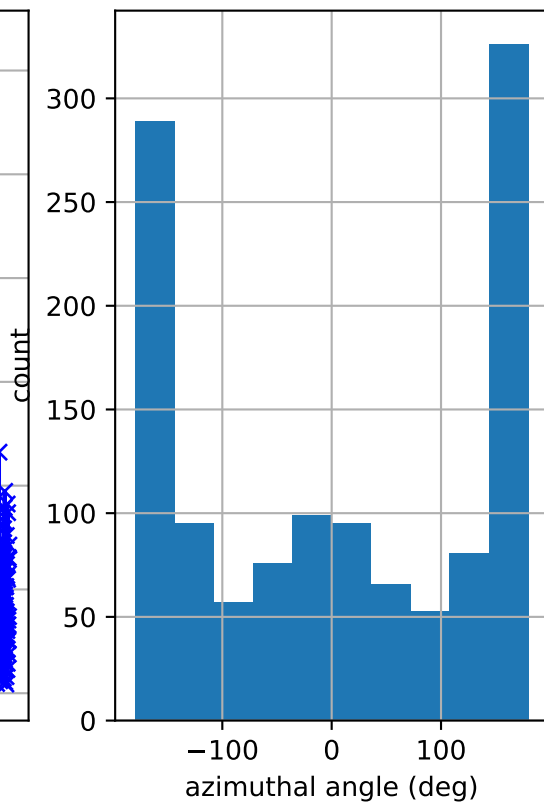
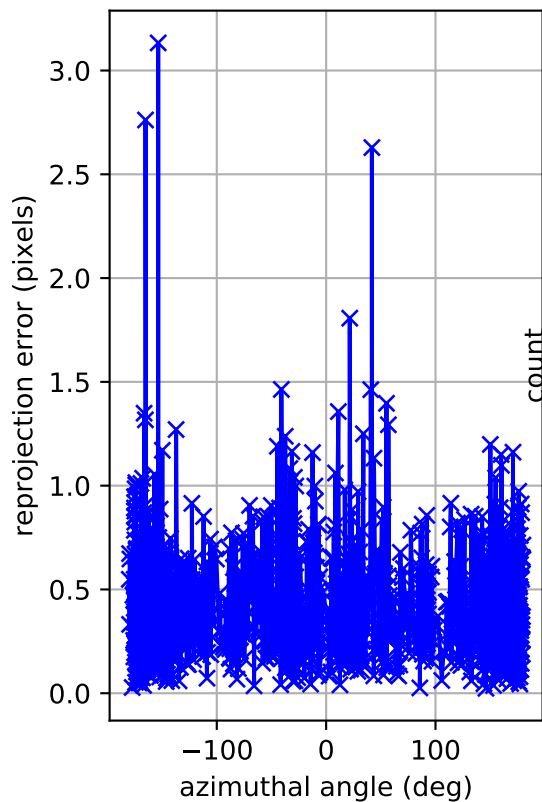
cam0: reprojection errors



cam1: polar error



cam1: azimuthal error



cam1: reprojection errors

