

Calibration results

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Camera-system parameters:

cam0 (/front_camera/left/image_raw):

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

distortion: [-0.18406713 0.02346203 -0.00158314 -0.00038236] +- [0.00031379 0.00008788 0.00006431 0.00005144]

projection: [570.82739843 578.67078331 650.15463074 360.46941937] +- [0.47250475 0.48017658 0.25255416 0.40989423]

reprojection error: [-0.000098, 0.000010] +- [1.479546, 1.057816]

cam1 (/front_camera/right/image_raw):

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

distortion: [-0.18271215 0.0228268 -0.00112649 0.00126445] +- [0.00032269 0.00008778 0.00006452 0.00005099]

projection: [570.46730976 577.58264367 613.93786177 336.95326153] +- [0.4862949 0.49224184 0.24986066 0.41388427]

reprojection error: [0.000108, 0.000006] +- [1.534745, 1.030945]

cam2 (/front_camera/rgb/image_raw):

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

distortion: [-0.19663189 0.0452768 0.0043848 0.00148525] +- [0.0008999 0.00073451 0.00016434 0.00013127]

projection: [1188.73815279 1191.74780249 966.18734615 561.35001839] +- [0.3735198 0.41115231 0.91030707 1.16172838]

reprojection error: [-0.000527, -0.001422] +- [0.926980, 0.741073]

baseline T_1_0:

q: [0.00283092 -0.0234248 -0.00336334 0.99971594] +- [0.00024518 0.00033293 0.00007396]

t: [-0.0726676 -0.00006652 0.00154296] +- [0.00004787 0.00003908 0.00007842]

baseline T_2_1:

q: [0.00322203 0.01267014 0.00035318 0.99991448] +- [0.00117034 0.0008675 0.00021988]

t: [0.03360175 0.00043354 -0.00424117] +- [0.00017991 0.00013549 0.0003863]

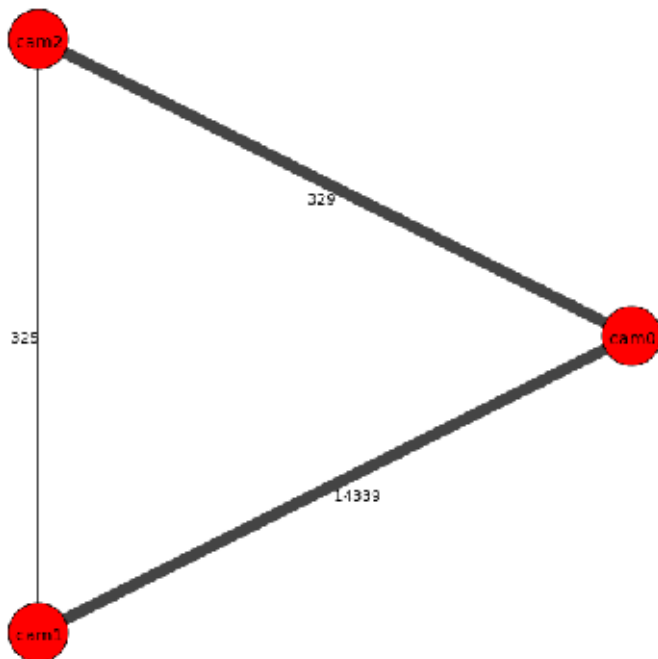
Target configuration

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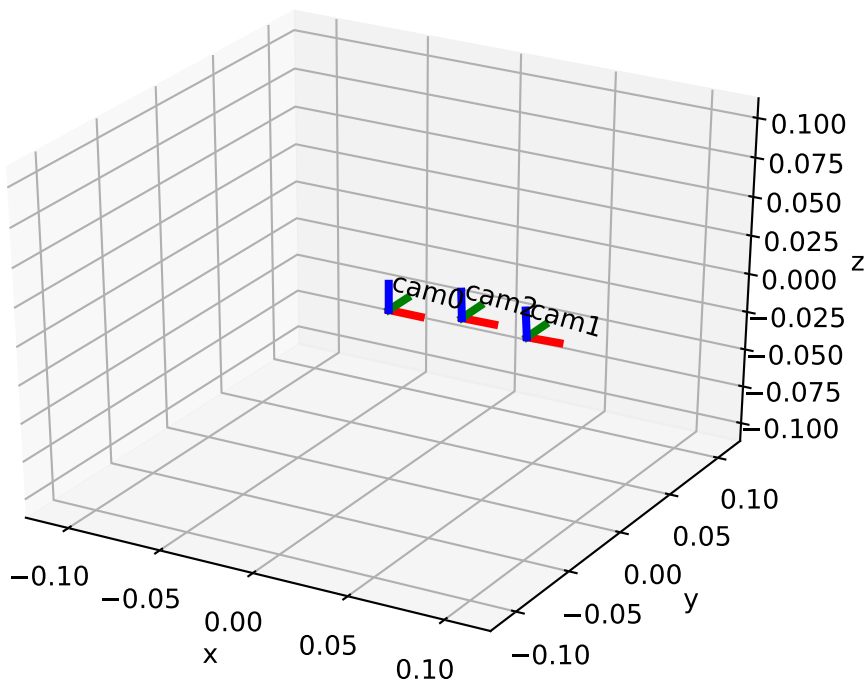
Type: aprilgrid

Tags:
Rows: 6
Cols: 6
Size: 0.0294 [m]
Spacing 0.00882 [m]

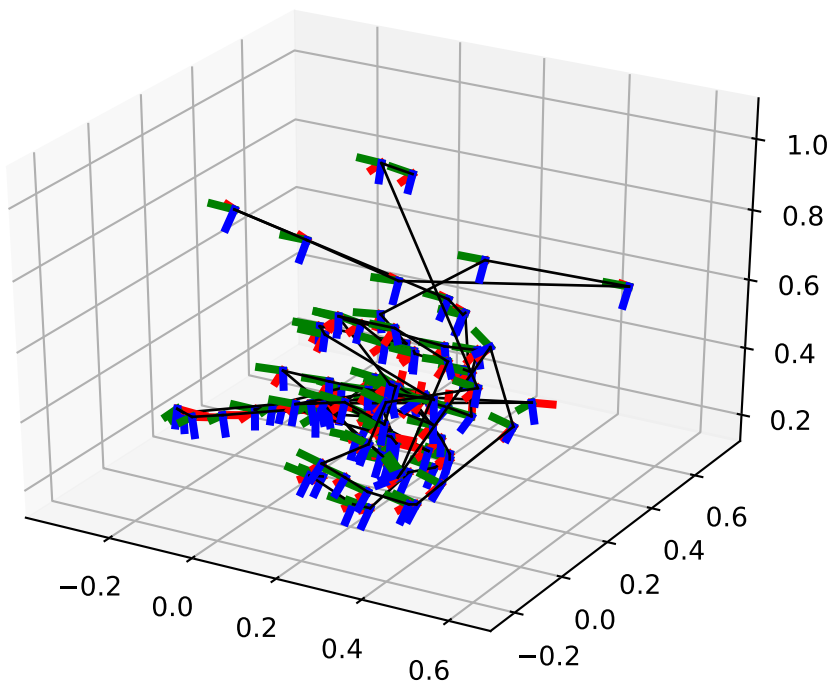
Inter-camera observations graph (edge weight=#mutual obs.)



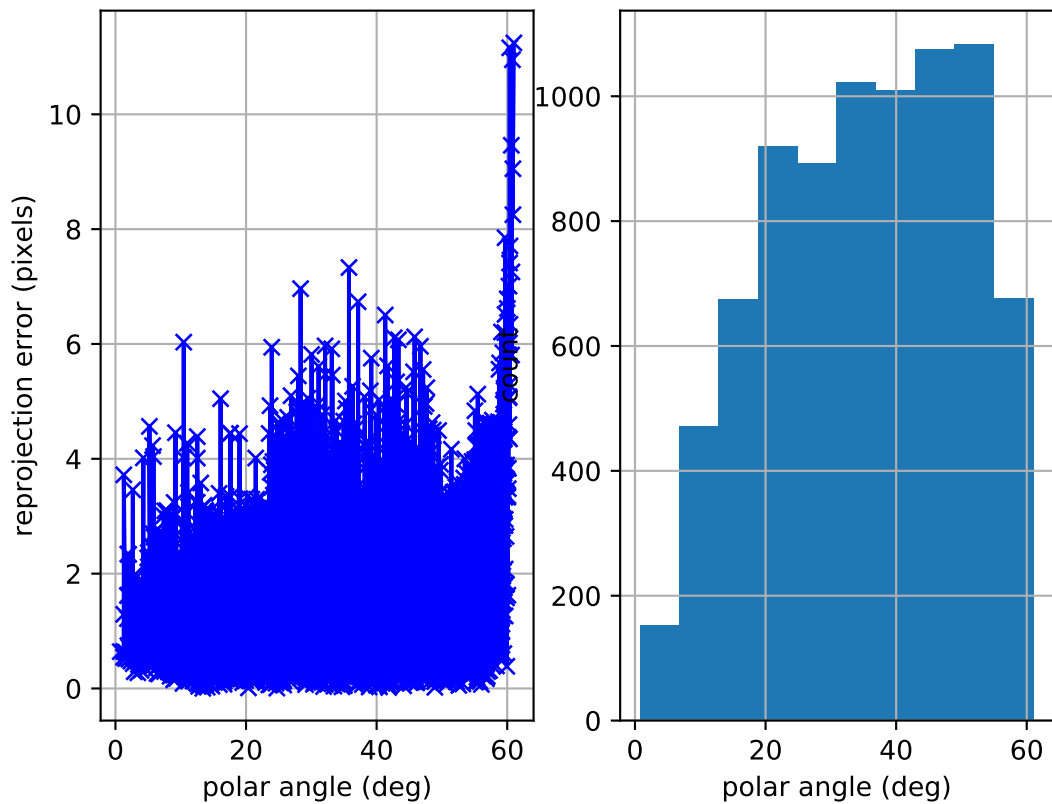
camera system



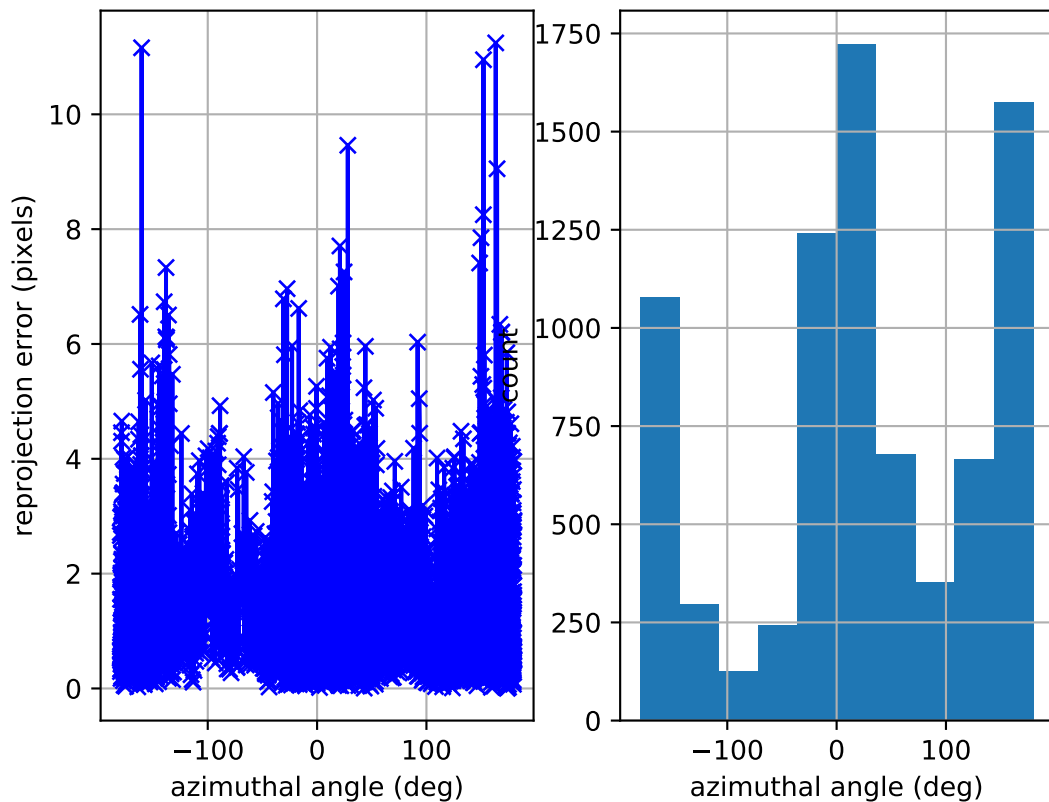
cam0: estimated poses



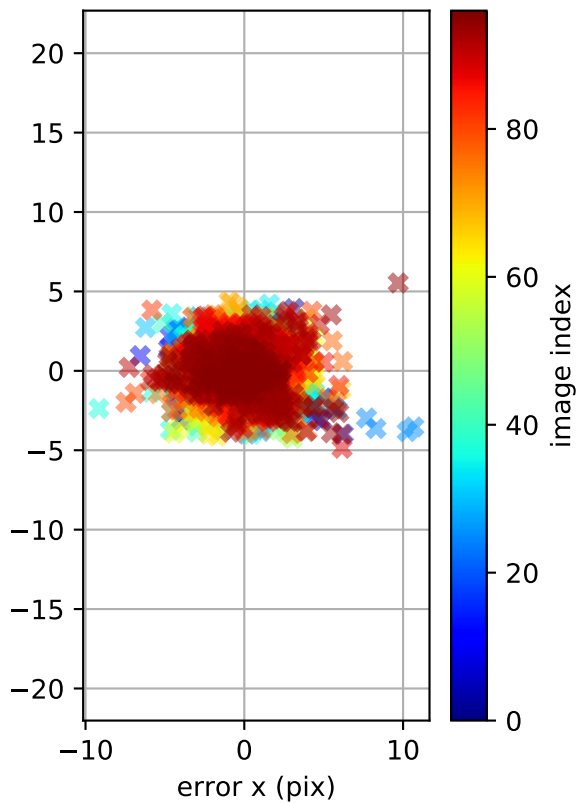
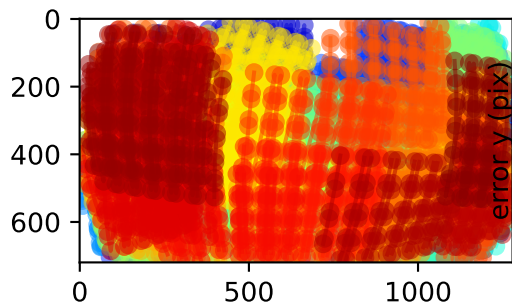
cam0: polar error



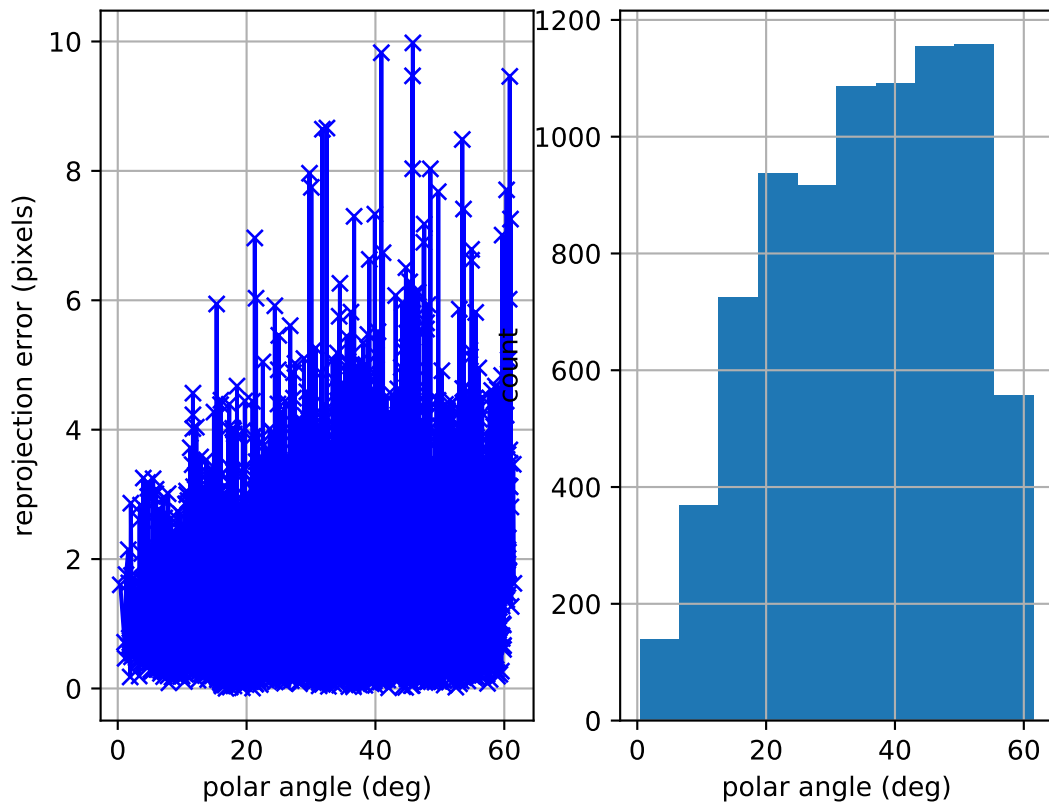
cam0: azimuthal error



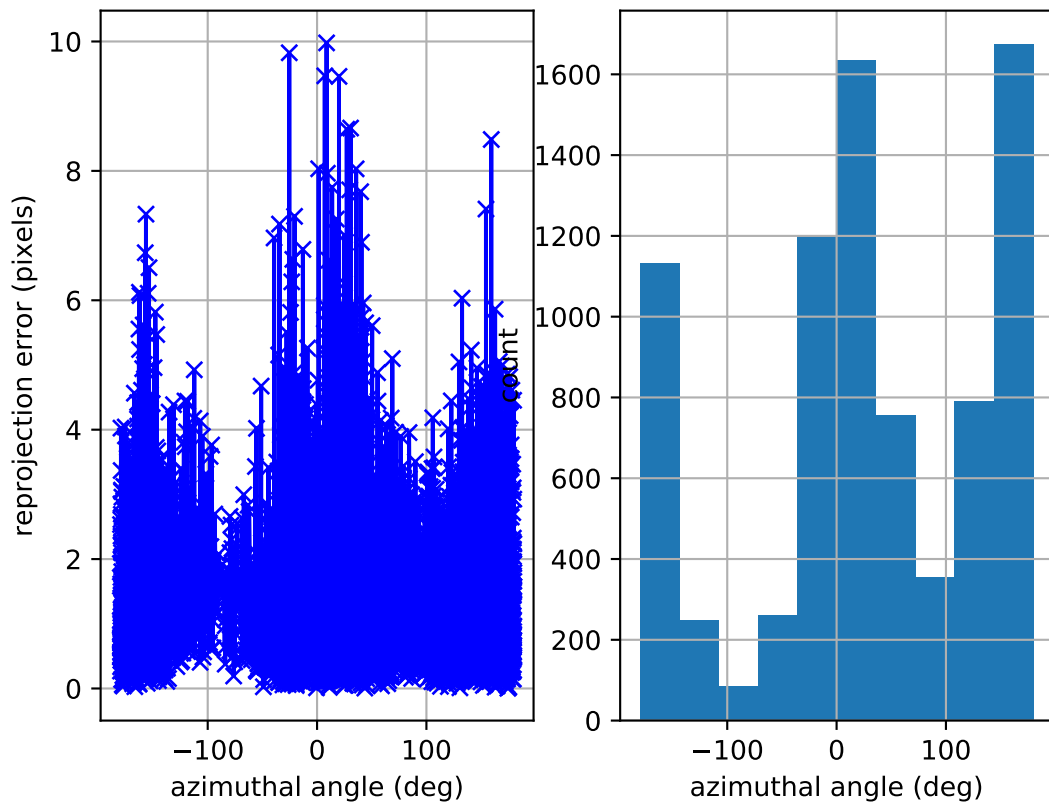
cam0: reprojection errors



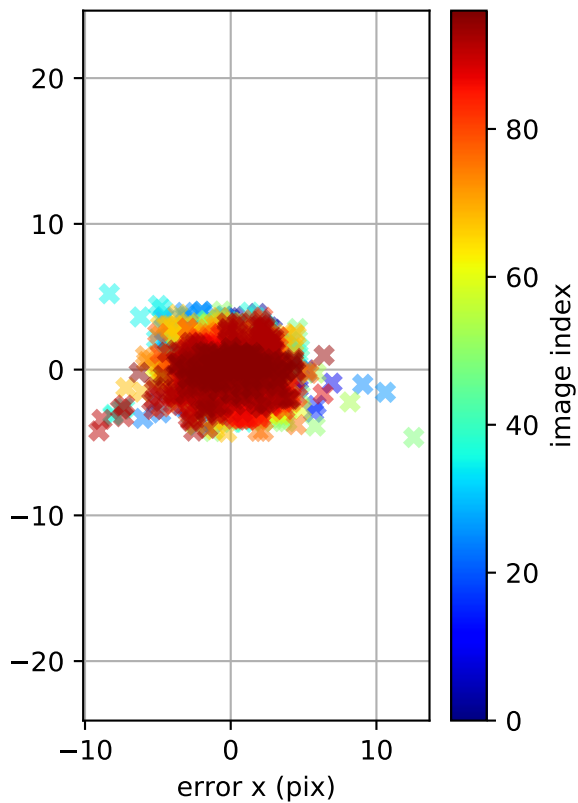
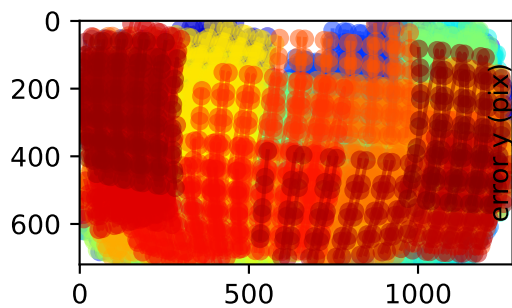
cam1: polar error



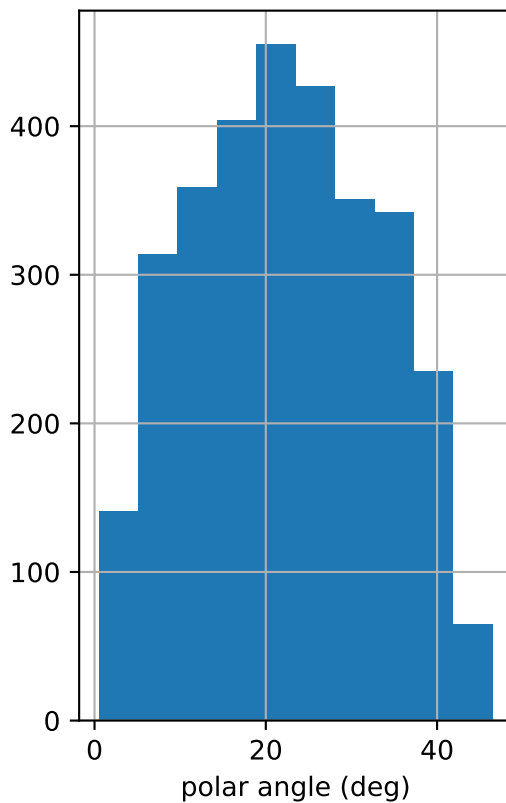
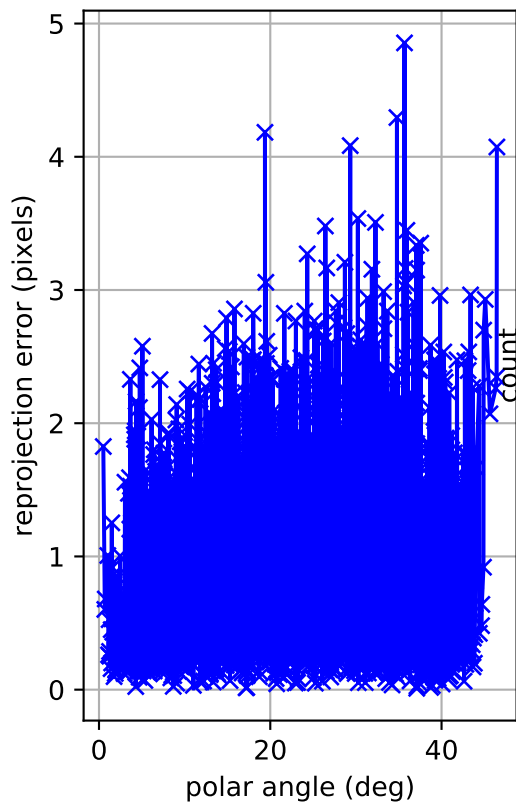
cam1: azimuthal error



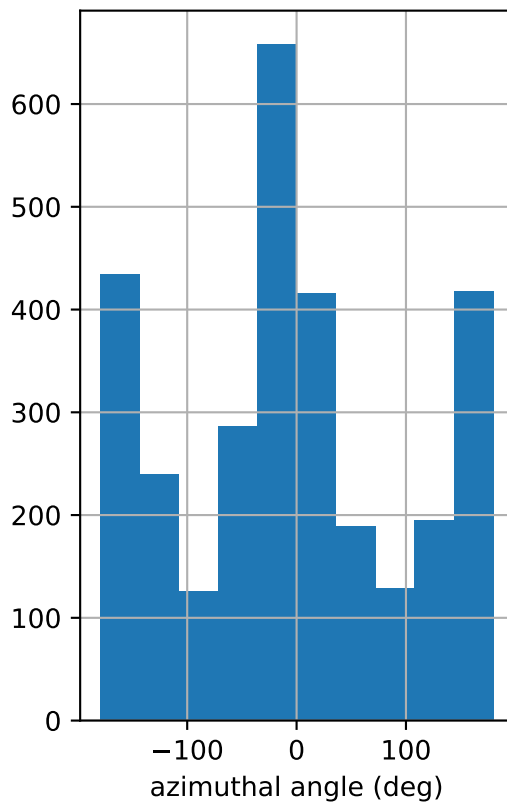
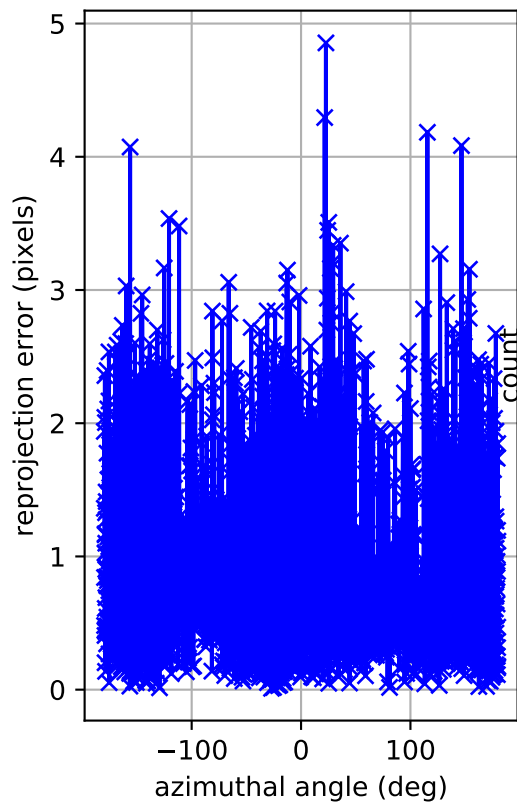
cam1: reprojection errors



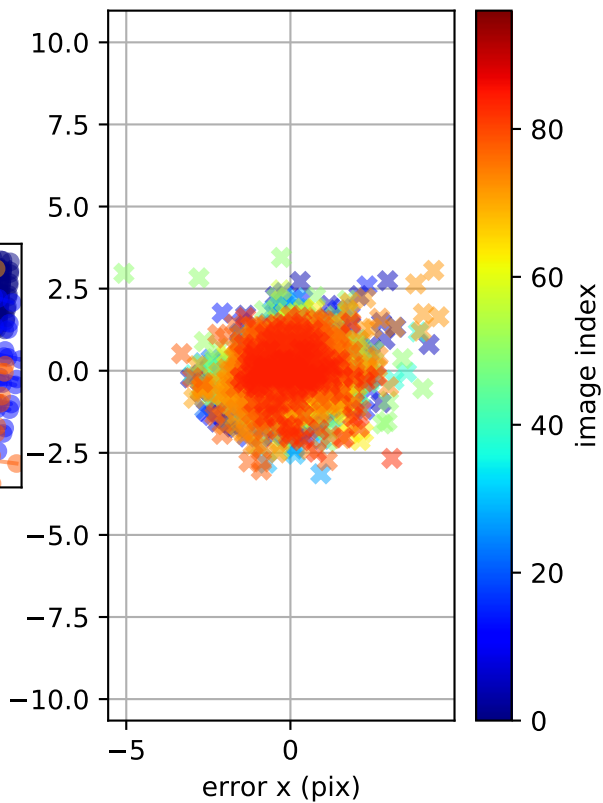
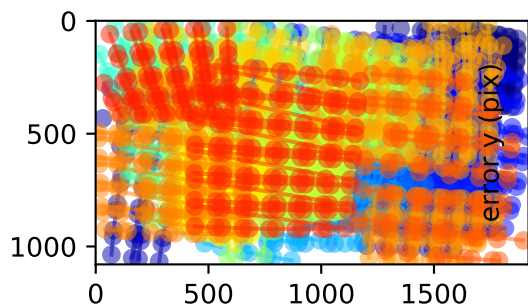
cam2: polar error



cam2: azimuthal error

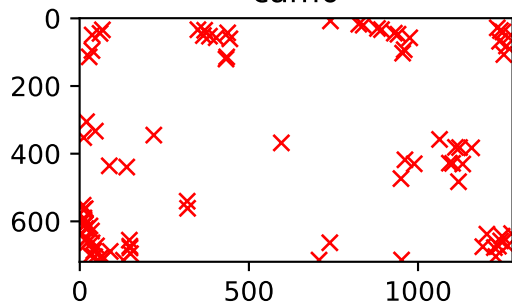


cam2: reprojection errors

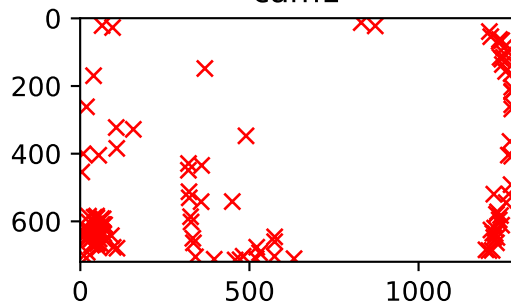


Location of removed outlier corners

cam0



cam1



cam2

