

Calibration results

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Camera-system parameters:

cam0 (/zed/zed_node/left/color/rect/image):

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

distortion: [0.01262954 -0.00298474 0.00047561 0.00139321] +- [0.00102716 0.00058366 0.00030815 0.0003995]

projection: [265.24697301 265.17067339 324.07516347 179.05260374] +- [0.43017192 0.41595683 0.41558012 0.33261472]

reprojection error: [-0.000002, 0.000000] +- [0.205031, 0.156832]

cam1 (/zed/zed_node/right/color/rect/image):

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

distortion: [0.01174266 -0.00287155 0.00035926 -0.00098104] +- [0.00099812 0.00054009 0.00030484 0.00039538]

projection: [265.35803773 265.19840955 321.45774447 178.82754834] +- [0.41671518 0.40841047 0.41507628 0.32656008]

reprojection error: [0.000002, -0.000000] +- [0.174498, 0.151922]

baseline T_1_0:

q: [0.00000043 -0.00444795 -0.00010651 0.9999901] +- [0.00053022 0.0010797 0.00014344]

t: [-0.11952105 0.0000799 0.00038763] +- [0.00010625 0.00009794 0.00026316]

Target configuration

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Type: aprilgrid

Tags:

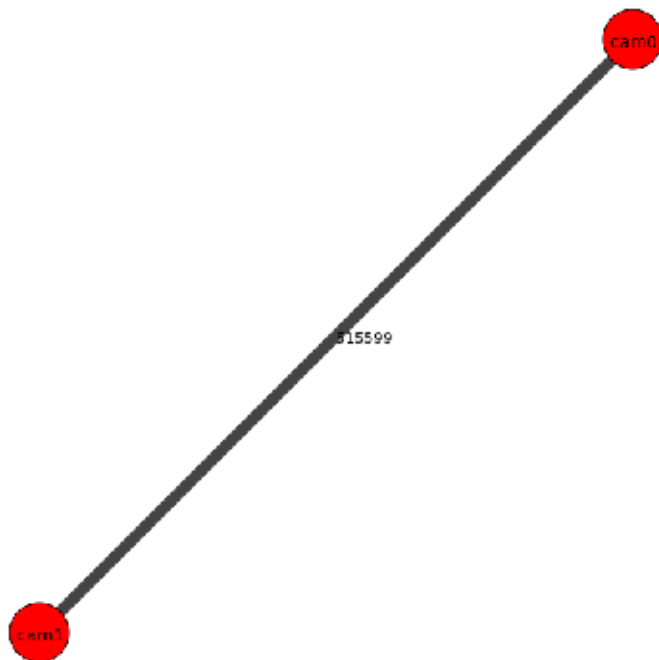
Rows: 6

Cols: 6

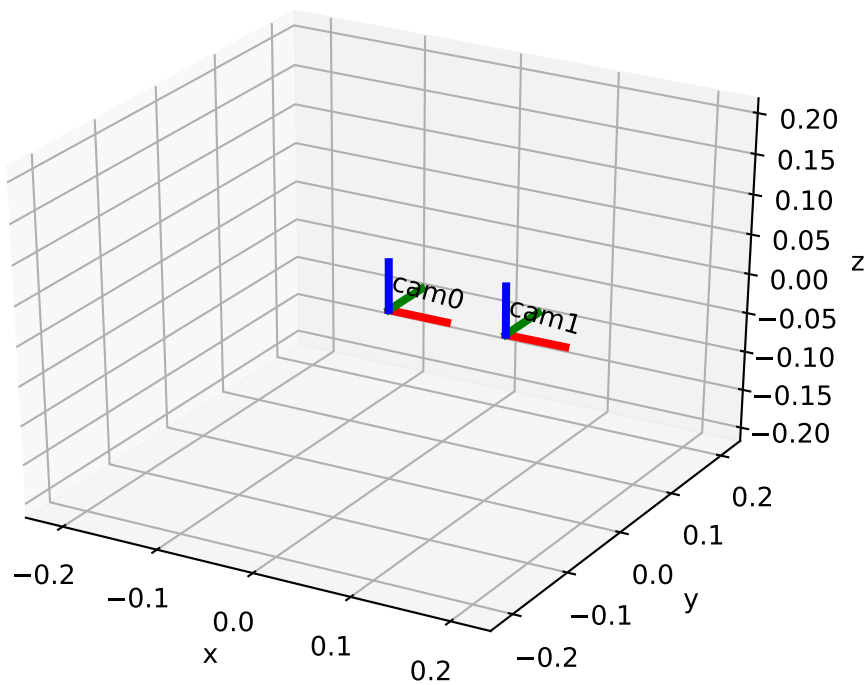
Size: 0.0445 [m]

Spacing 0.013171999999999998 [m]

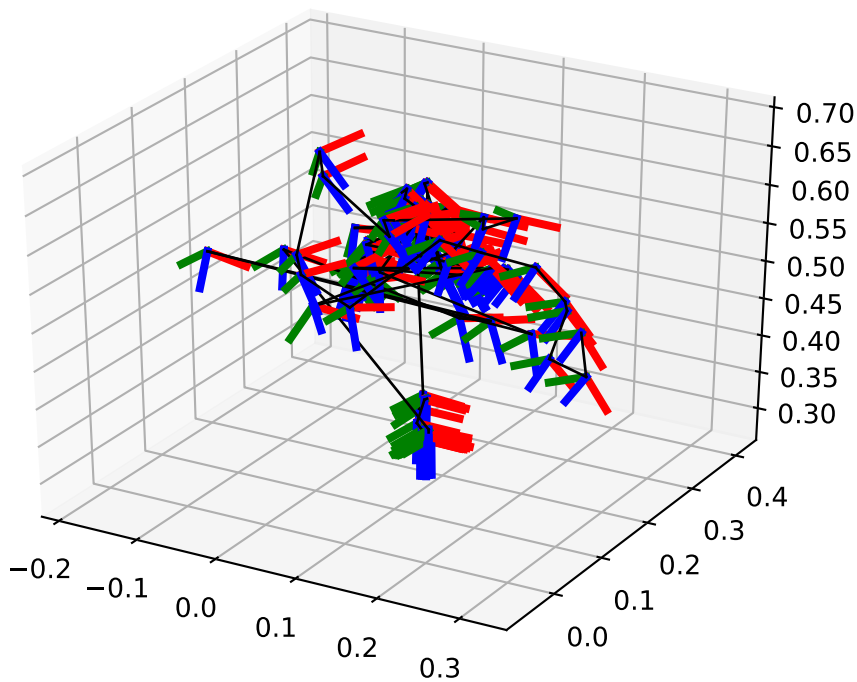
Inter-camera observations graph (edge weight=#mutual obs.)



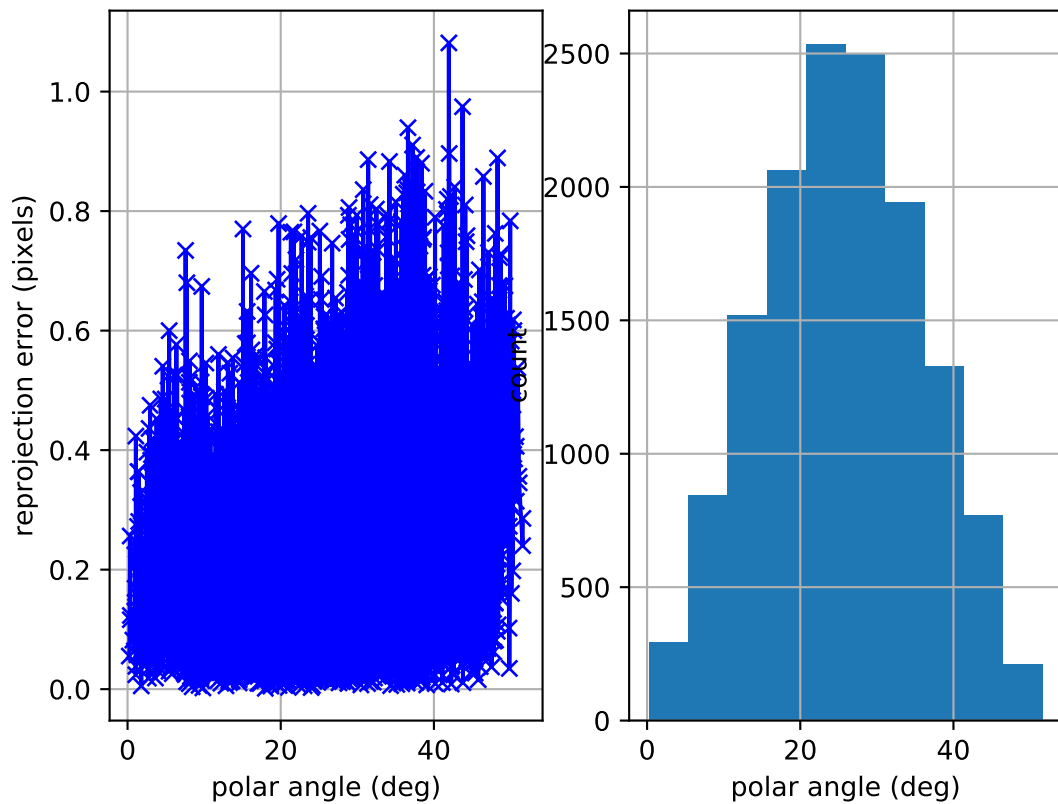
camera system



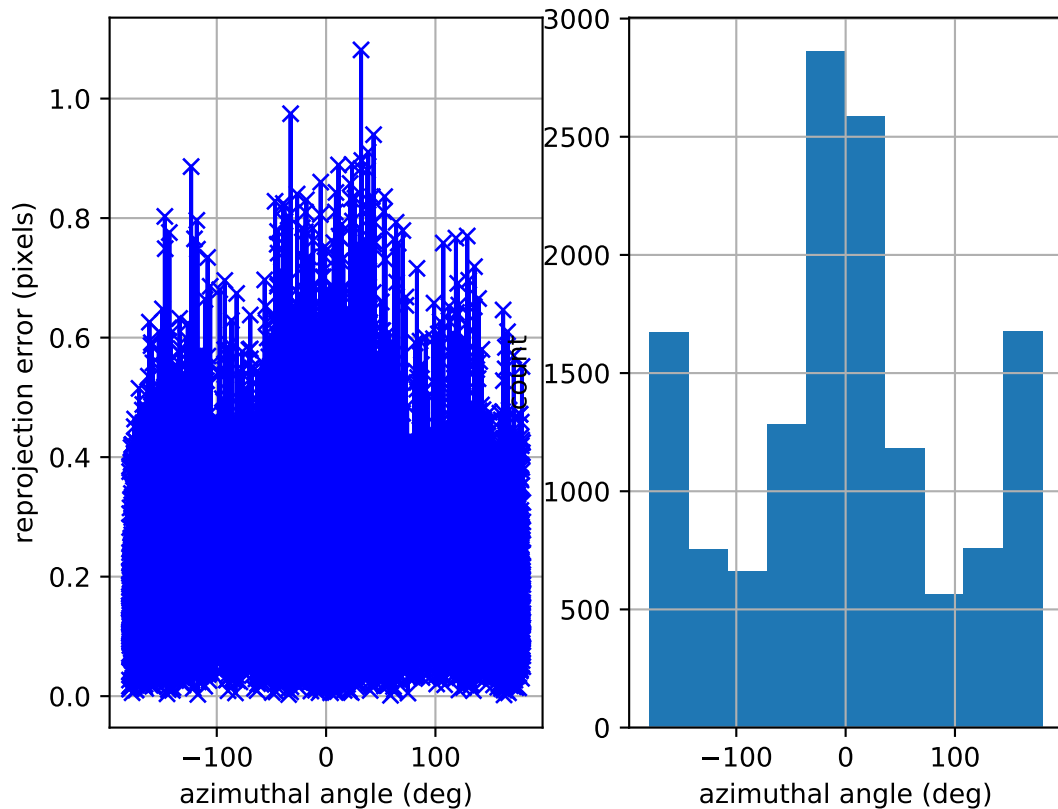
cam0: estimated poses



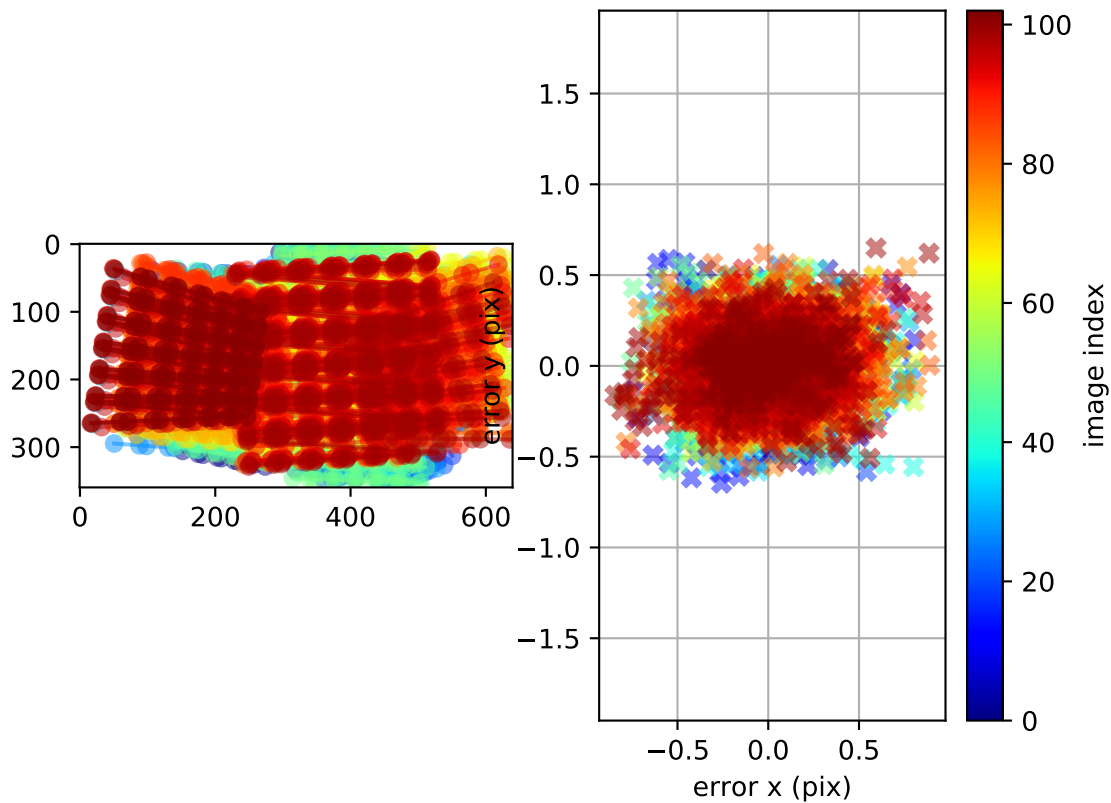
cam0: polar error



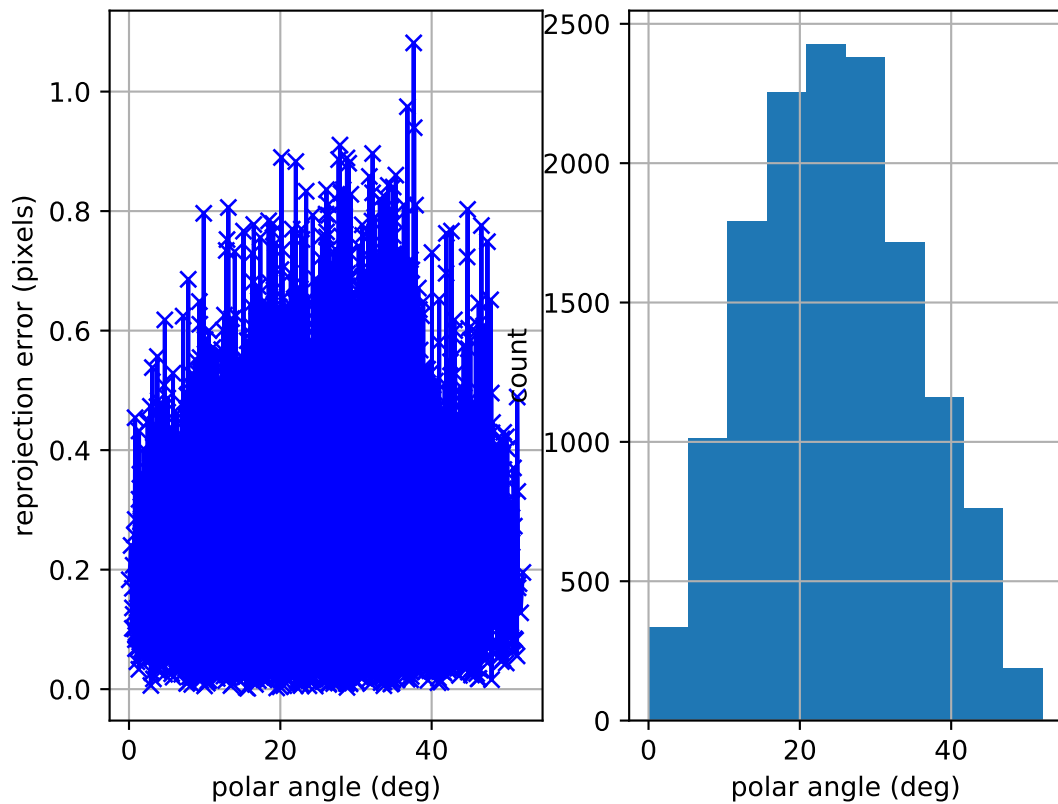
cam0: azimuthal error



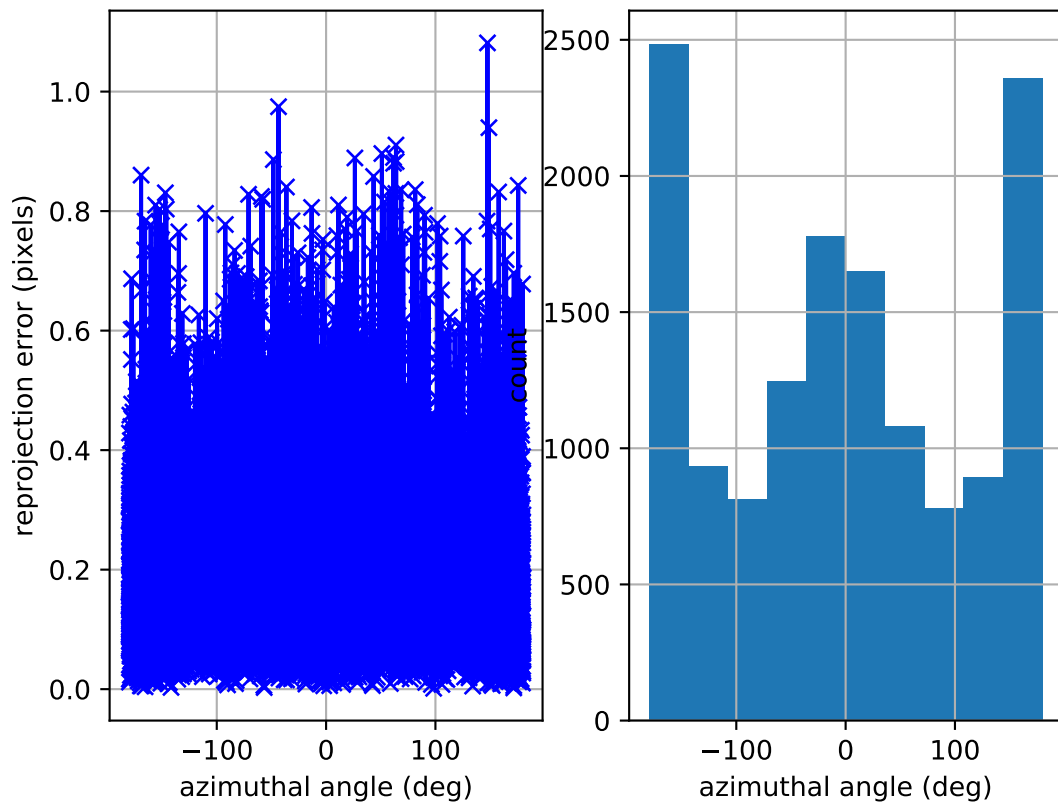
cam0: reprojection errors



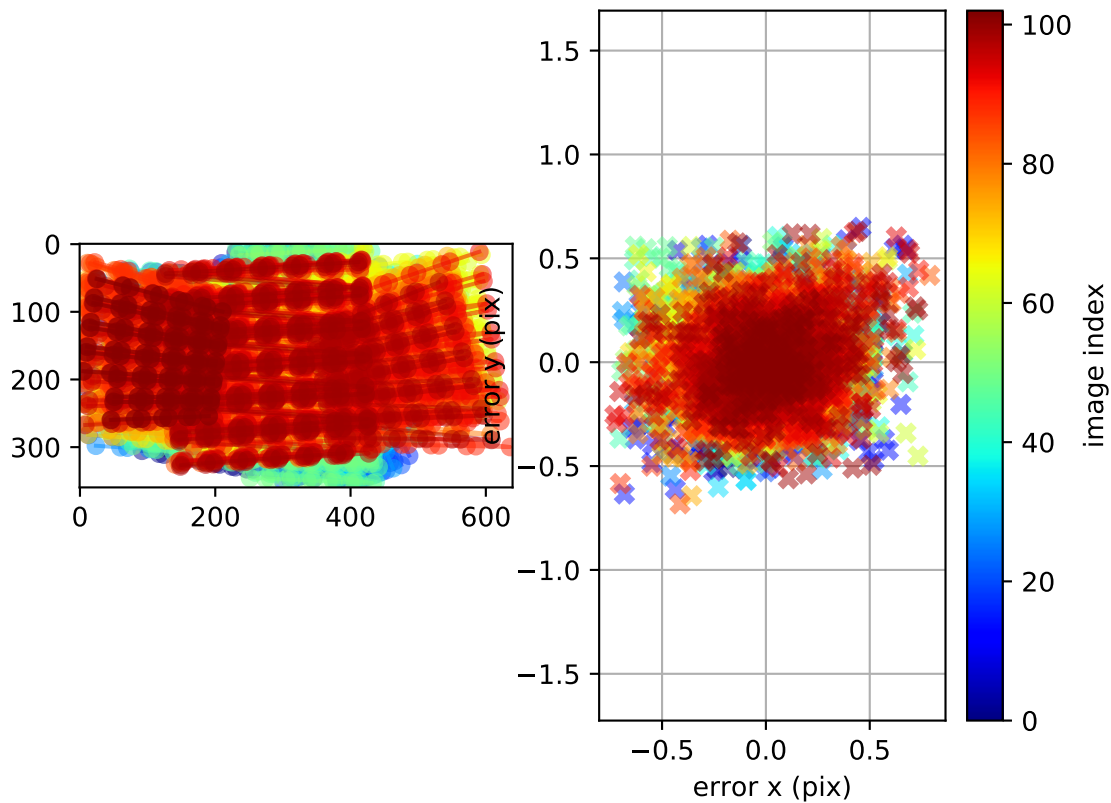
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

