

Calibration results

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Camera-system parameters:

cam0 (/infra_left):

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

distortion: [0.00284743 -0.00475175 -0.00028688 0.00090006] +- [0.00234498 0.00313612 0.00035244 0.00057652]

projection: [419.74891374 420.08253249 424.90321933 240.27448803] +- [0.18836455 0.19941131 0.7673425
0.35834447]

reprojection error: [0.000005, 0.000001] +- [0.047288, 0.039880]

cam1 (/infra_right):

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

distortion: [0.00206843 -0.00445107 -0.00032684 0.00029441] +- [0.00204848 0.00213458 0.00034237 0.00057377]

projection: [419.74349142 420.10618156 423.99575322 240.32063187] +- [0.19804255 0.19333272 0.74699637
0.36457454]

reprojection error: [-0.000001, -0.000000] +- [0.045070, 0.042340]

baseline T_1_0:

q: [-0.00003038 -0.00082428 0.00004041 0.99999966] +- [0.00091523 0.00187892 0.00012858]

t: [-0.04998339 0.00004831 -0.00017769] +- [0.00007901 0.00007591 0.00030394]

Target configuration

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Type: checkerboard

Rows

Count: 11

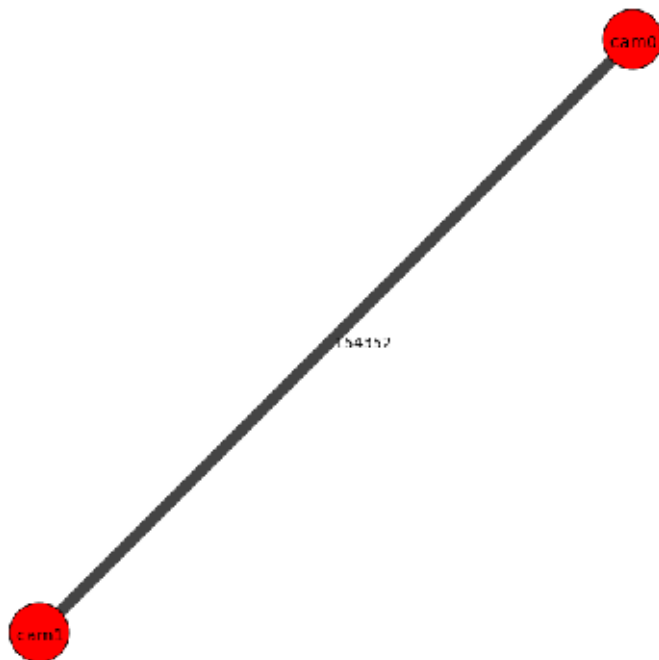
Distance: 0.02 [m]

Cols

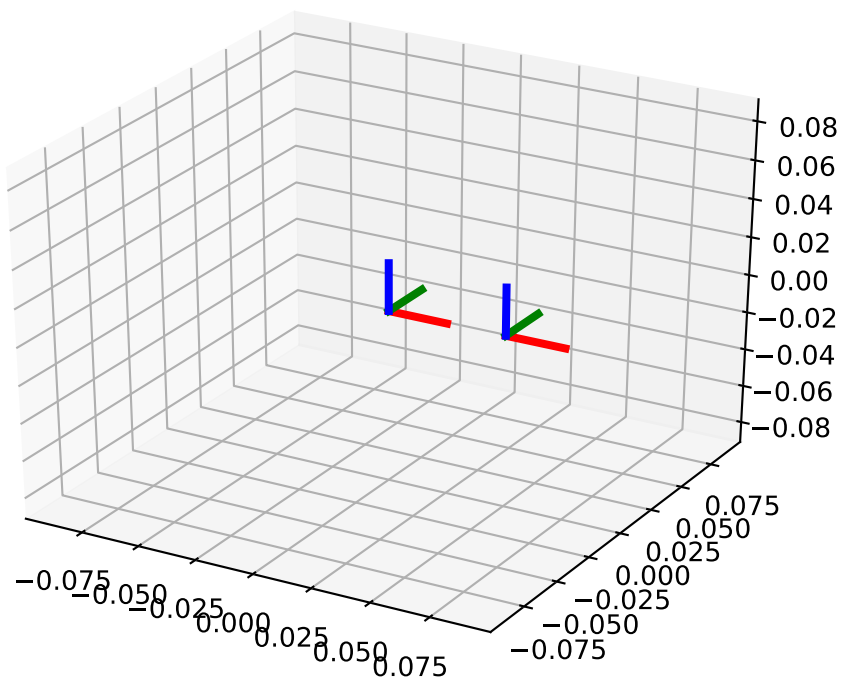
Count: 8

Distance: 0.02 [m]

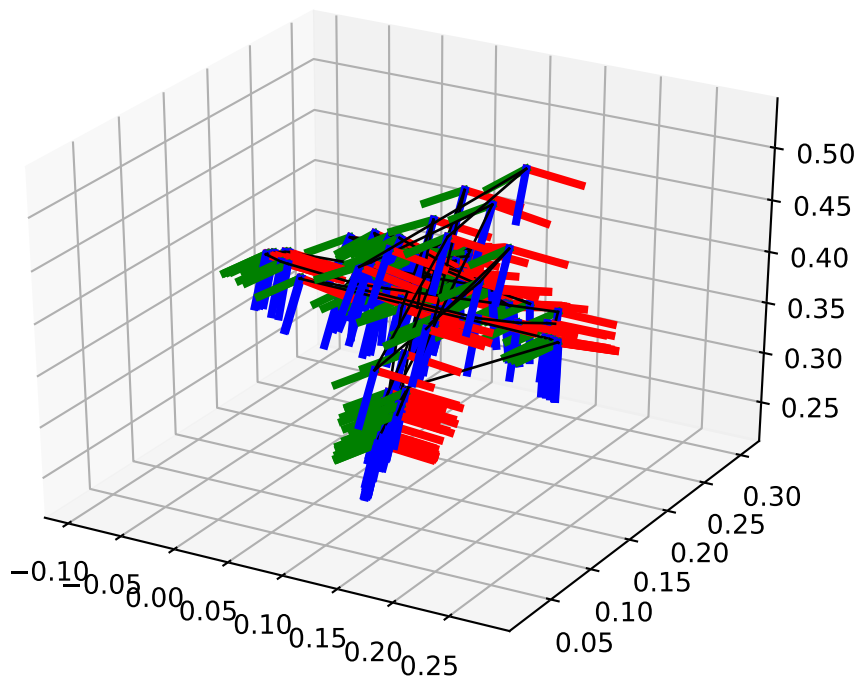
Inter-camera observations graph (edge weight=#mutual obs.)



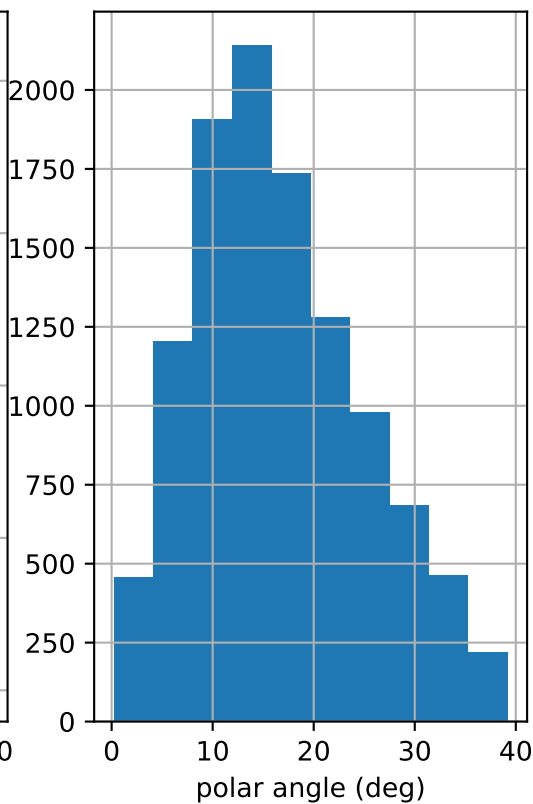
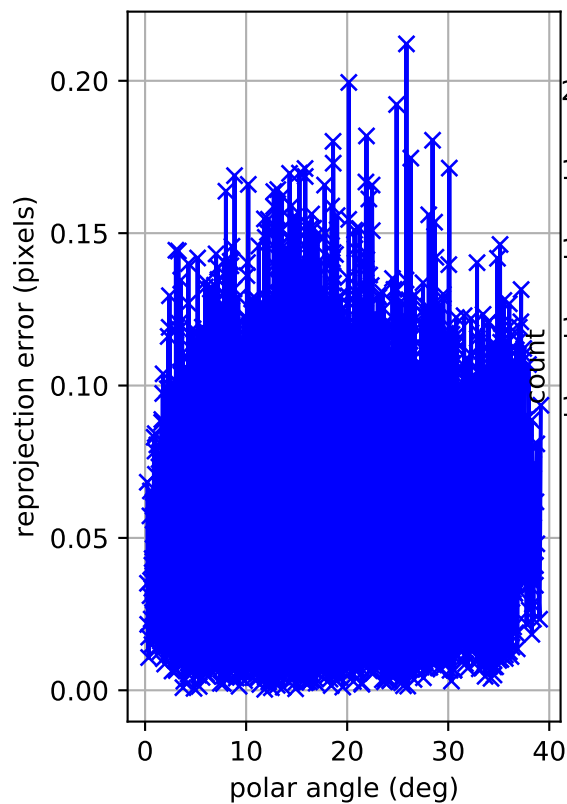
camera system



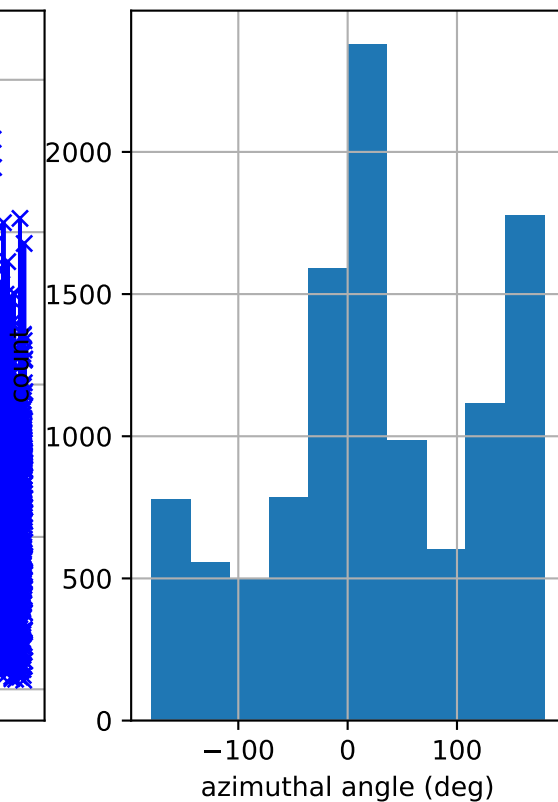
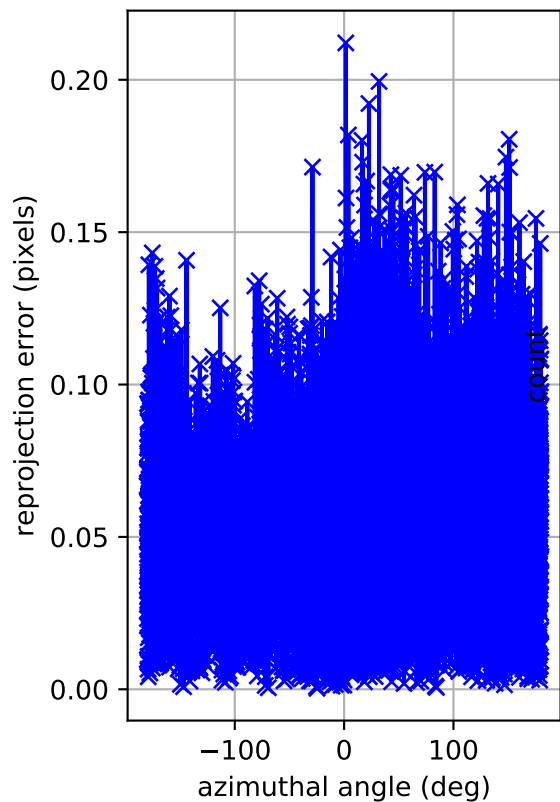
cam0: estimated poses



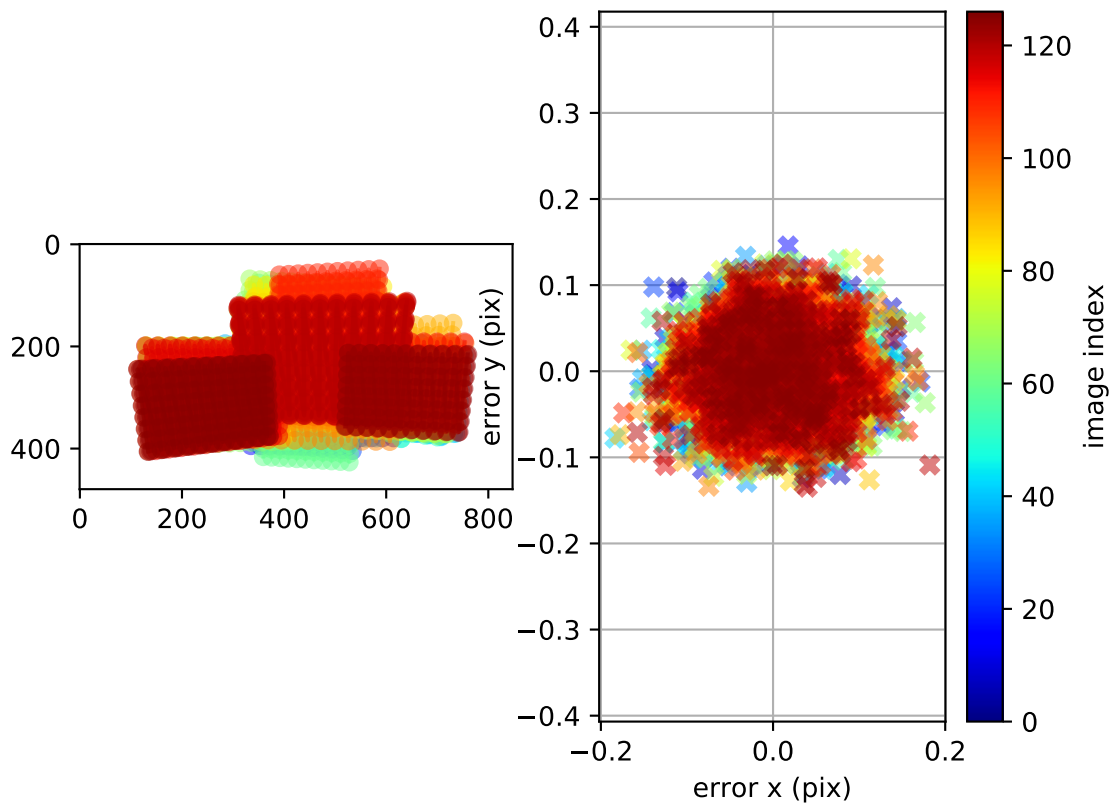
cam0: polar error



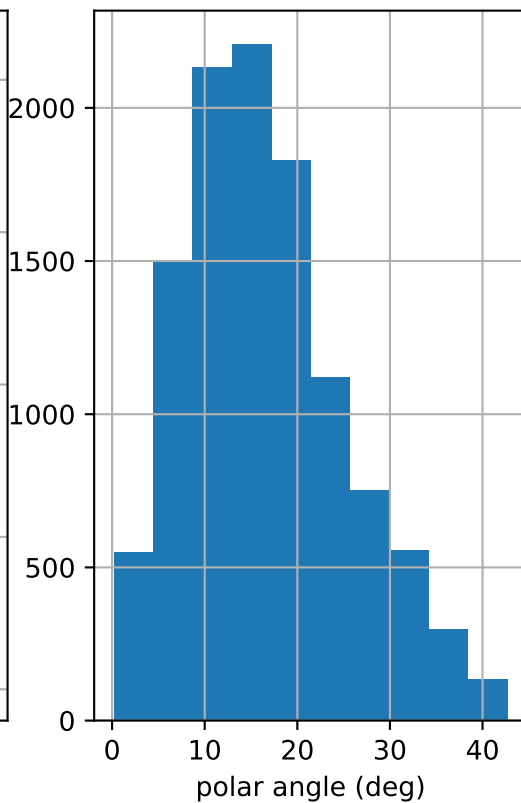
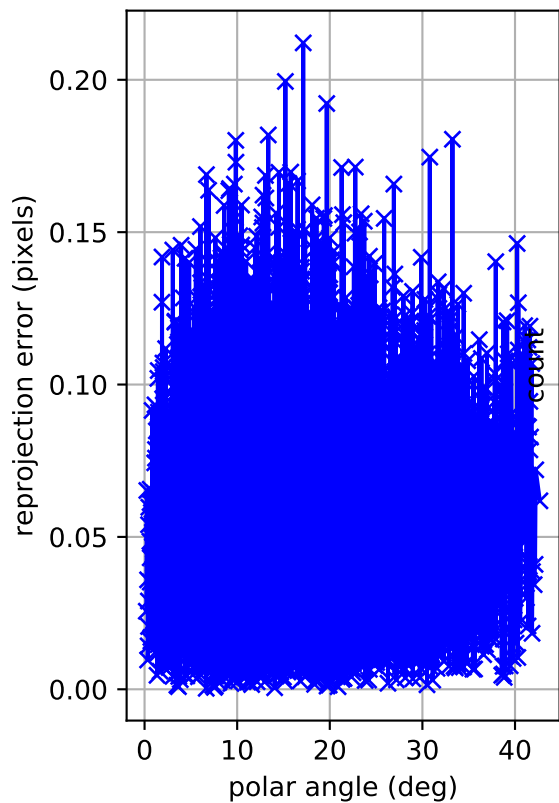
cam0: azimuthal error



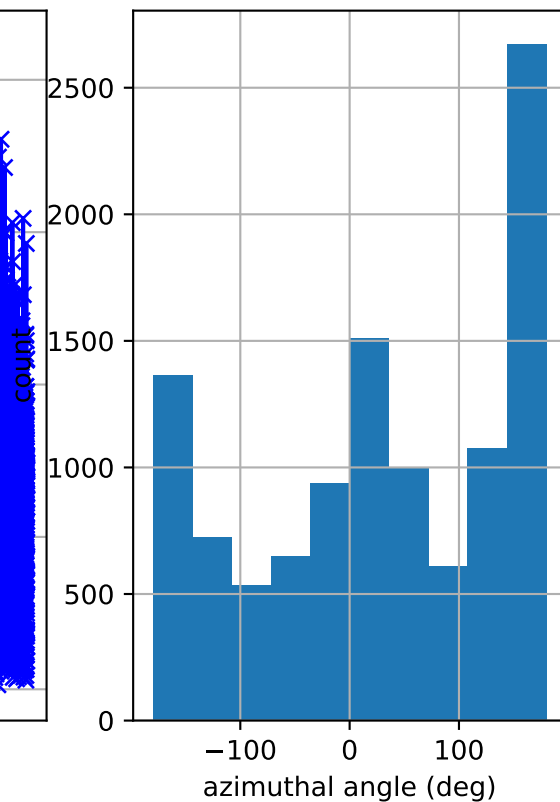
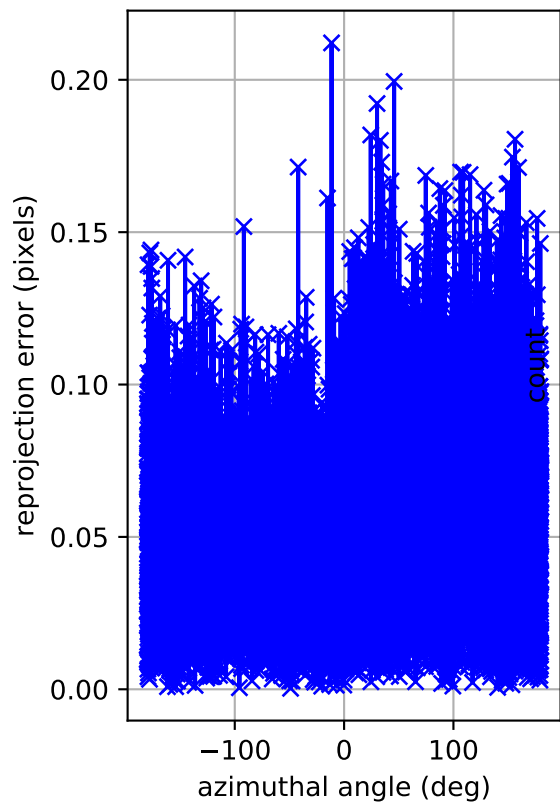
cam0: reprojection errors



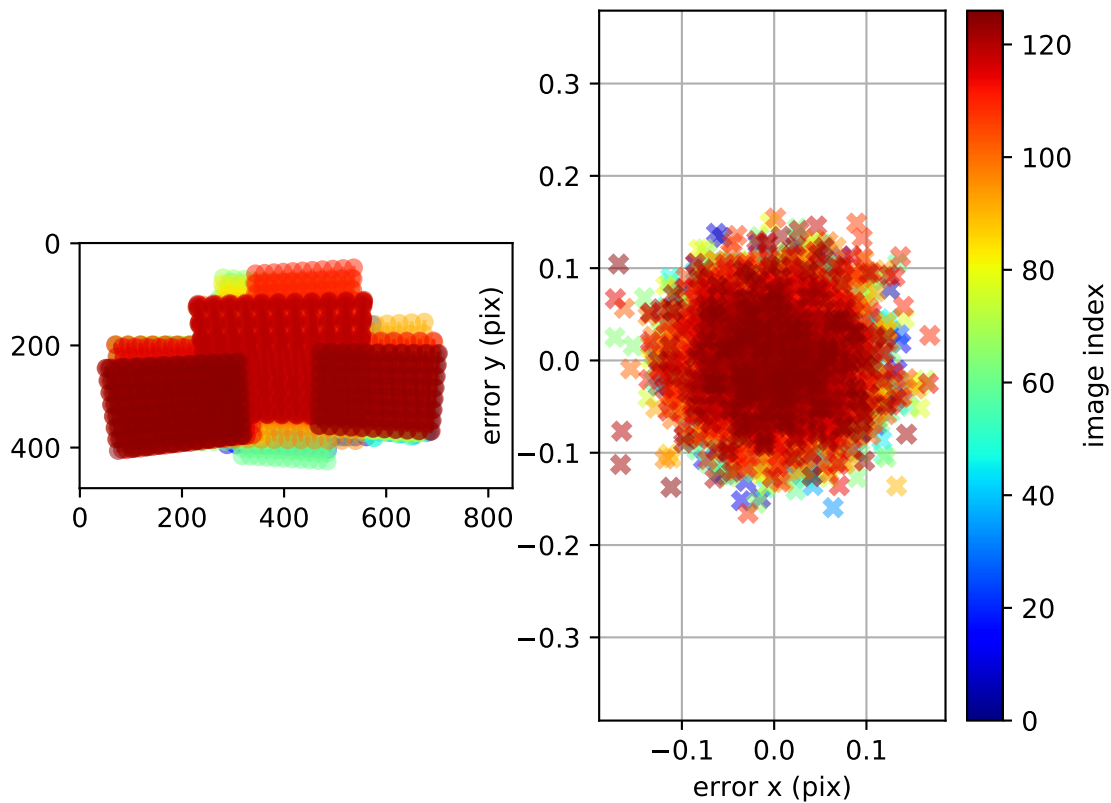
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

