

Calibration results

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Camera-system parameters:

cam0 (/front_camera/left/image):

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

distortion: [-0.00145828 -0.02183518 0.0206765 -0.00564608] +- [0.00174365 0.00429588 0.00406794 0.00132163]

projection: [587.2901024 587.11545497 617.04731924 356.04404455] +- [0.09994134 0.09849422 0.11061531 0.05664211]

reprojection error: [-0.000028, -0.000011] +- [0.318362, 0.273647]

cam1 (/front_camera/right/image):

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

distortion: [0.00759408 -0.04456217 0.05003868 -0.01573533] +- [0.00154431 0.00413537 0.00419164 0.00144528]

projection: [577.62650628 577.9573 612.75449225 384.88975812] +- [0.03466212 0.03502519 0.12080838 0.06512158]

reprojection error: [0.000046, -0.000008] +- [0.496280, 0.375596]

cam2 (/front_camera/rgb/image_color):

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

distortion: [0.00371836 -0.02577371 0.02278289 -0.00521423] +- [0.00188302 0.00467442 0.00450089 0.00149266]

projection: [581.09226932 581.31970527 661.6947313 365.83853351] +- [0.10909644 0.10813647 0.10606627 0.05709492]

reprojection error: [0.000027, -0.000009] +- [0.346692, 0.250431]

baseline T_1_0:

q: [0.00031663 0.00311587 -0.00320907 0.99998995] +- [0.00018771 0.0003649 0.00003829]

t: [-0.07526542 -0.00007574 -0.00017945] +- [-0.00002301 0.00002111 0.00004523]

baseline T_2_1:

q: [0.0041832 0.00024168 -0.0015584 0.99999001] +- [0.00018997 0.00034714 0.00003713]

t: [0.03806589 0.00012935 0.00001625] +- [0.00002221 0.00002123 0.00004284]

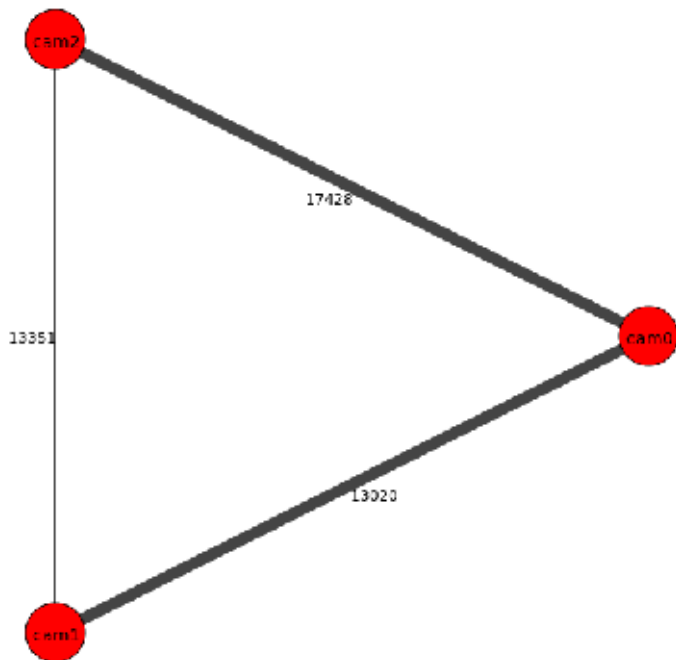
Target configuration

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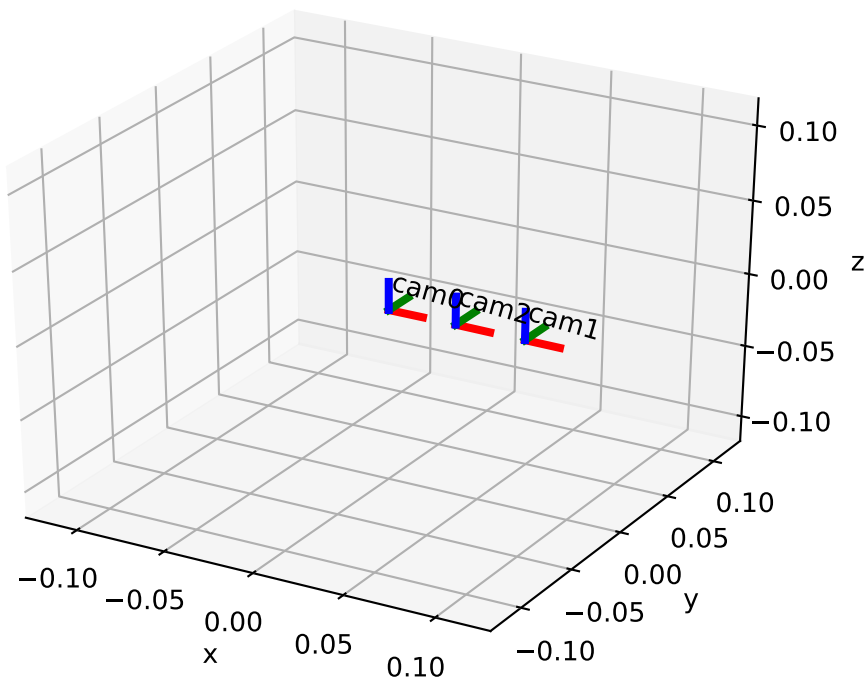
Type: aprilgrid

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

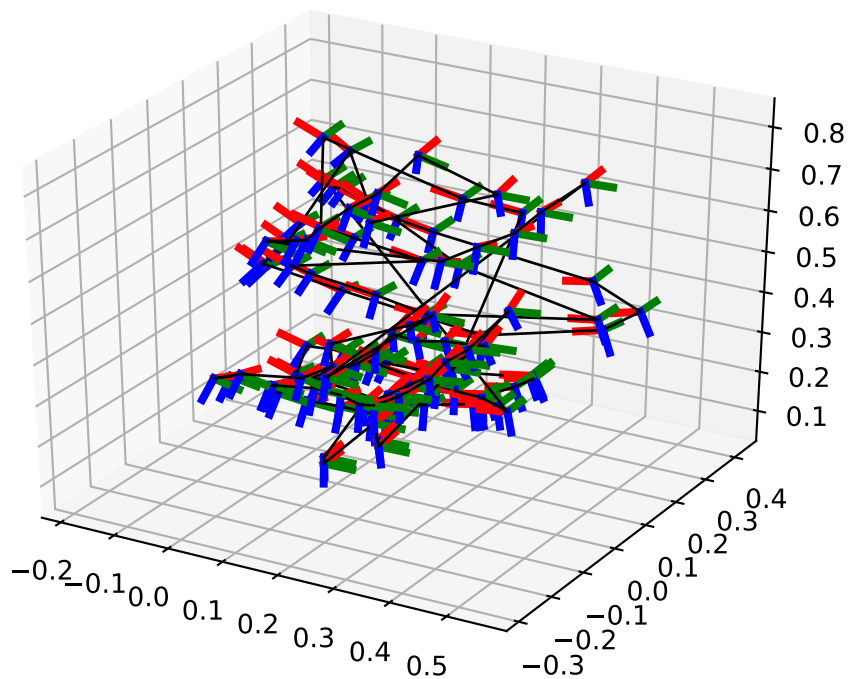
Inter-camera observations graph (edge weight=#mutual obs.)



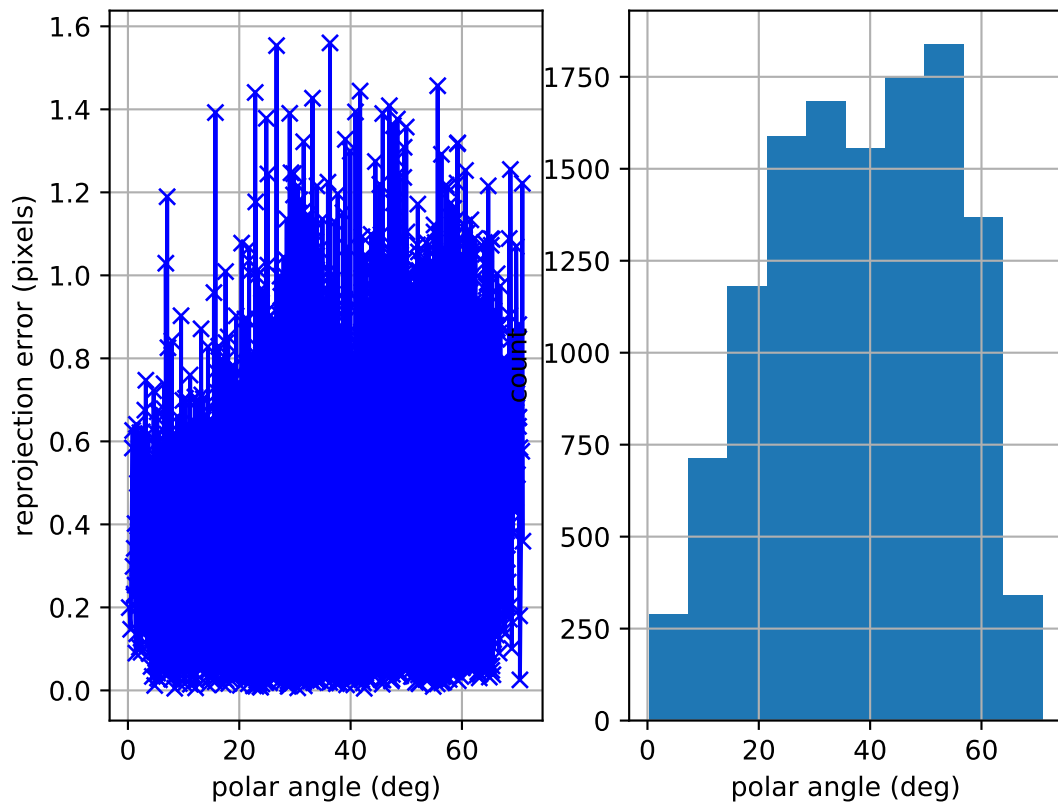
camera system



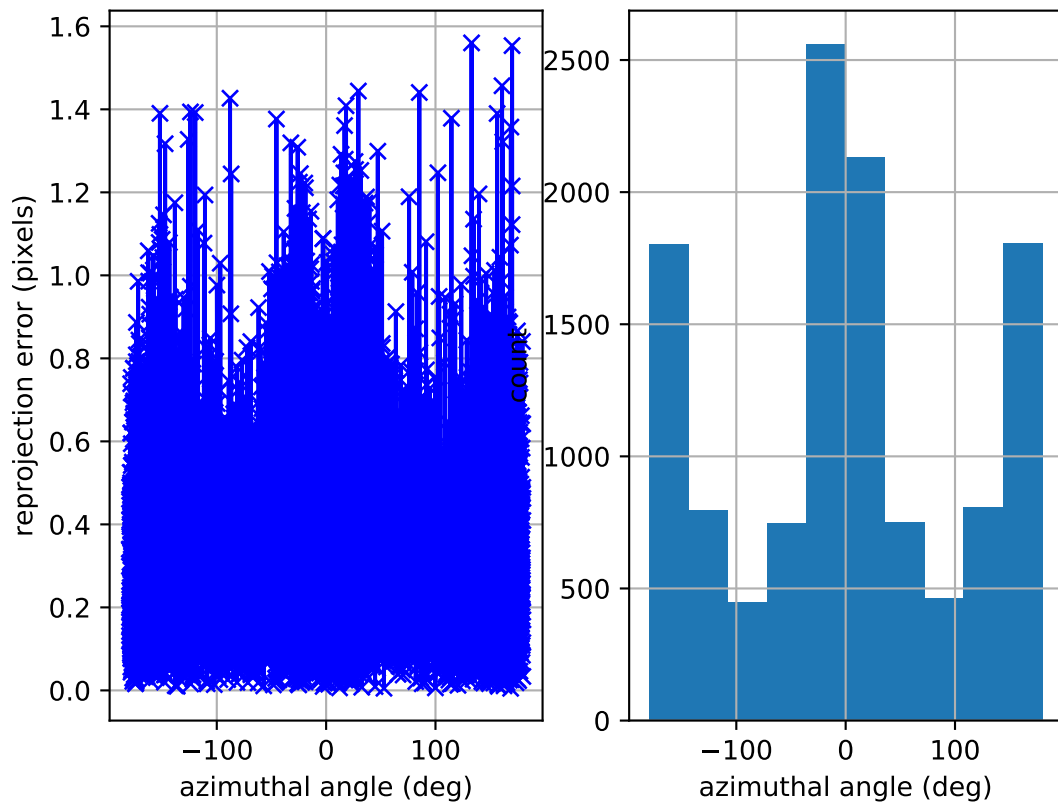
cam0: estimated poses



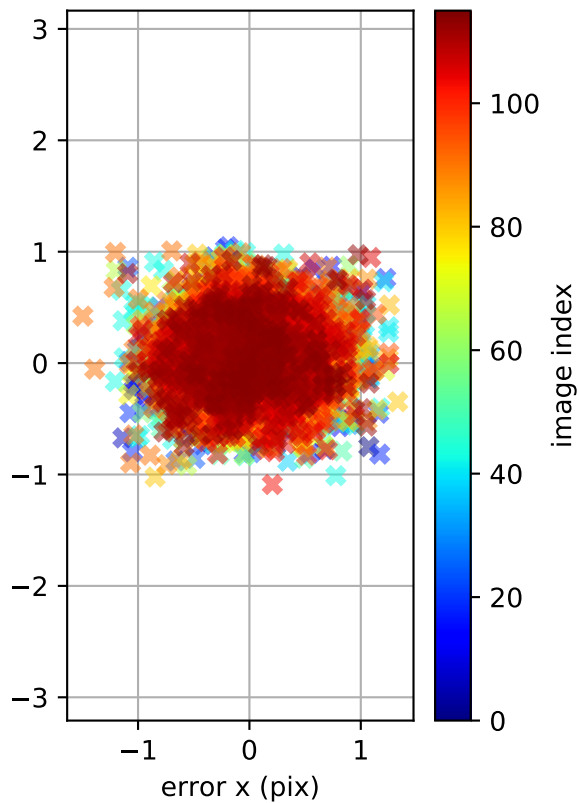
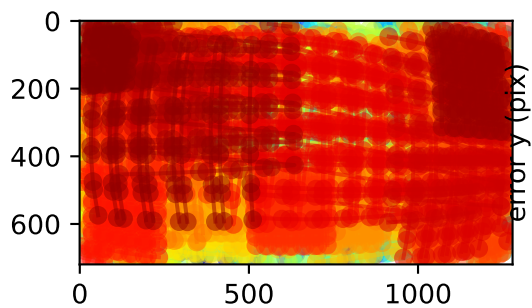
cam0: polar error



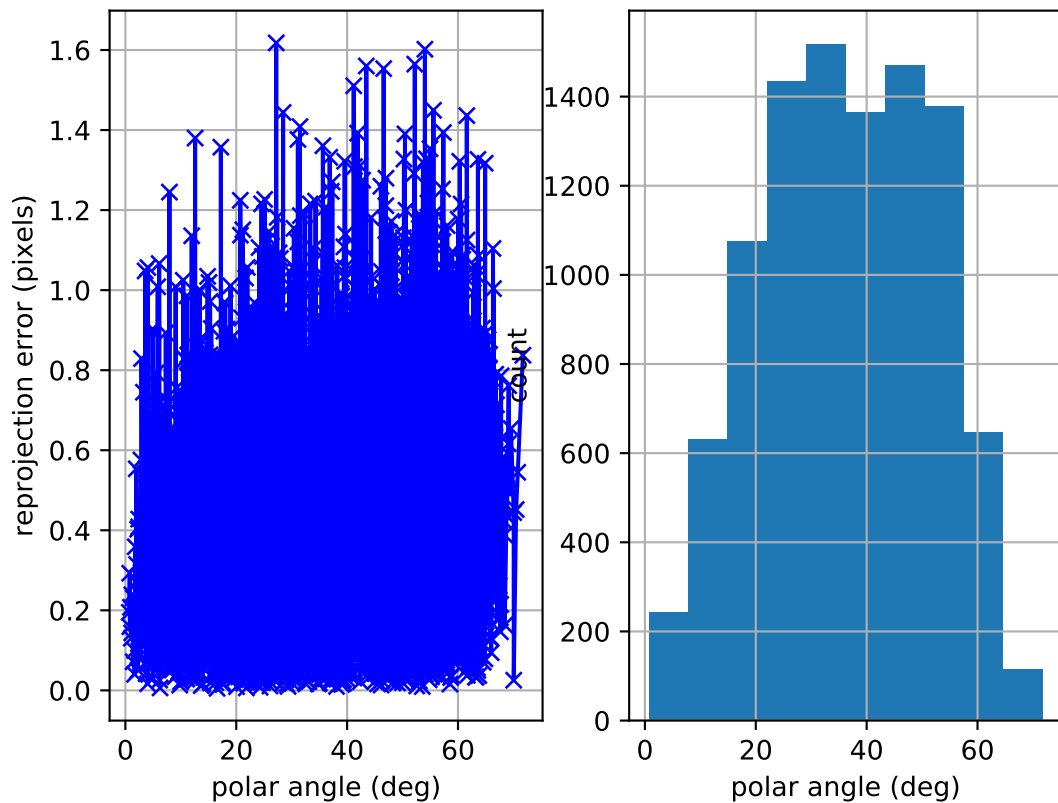
cam0: azimuthal error



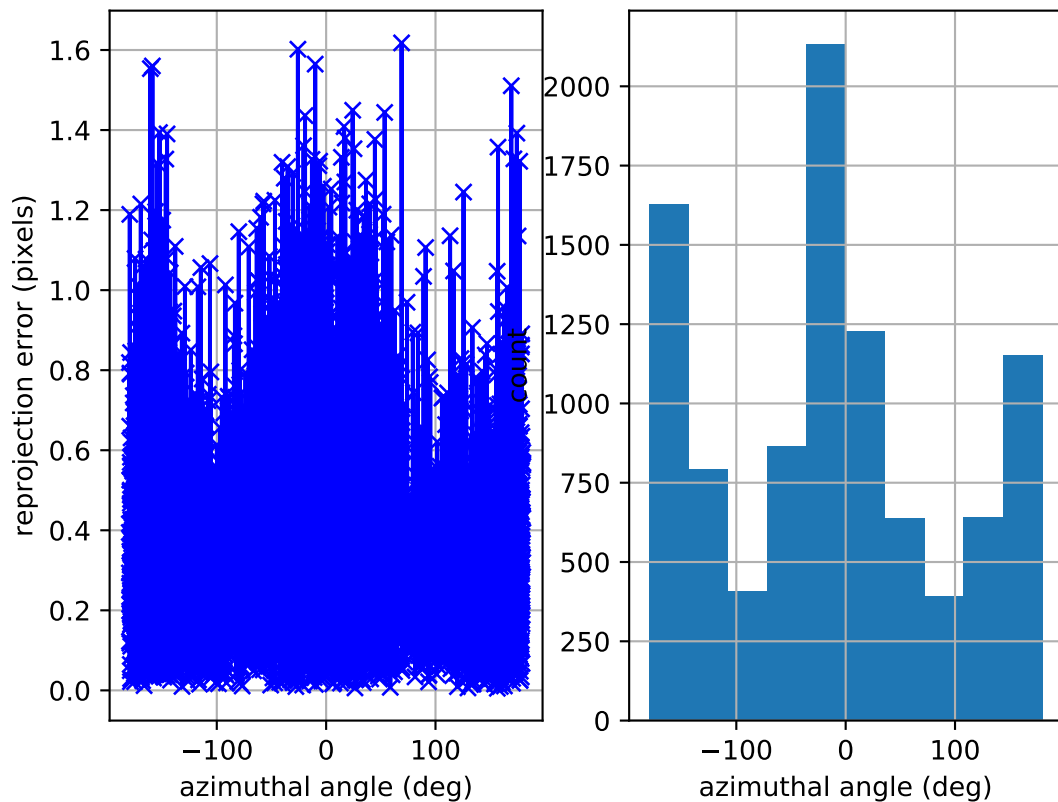
cam0: reprojection errors



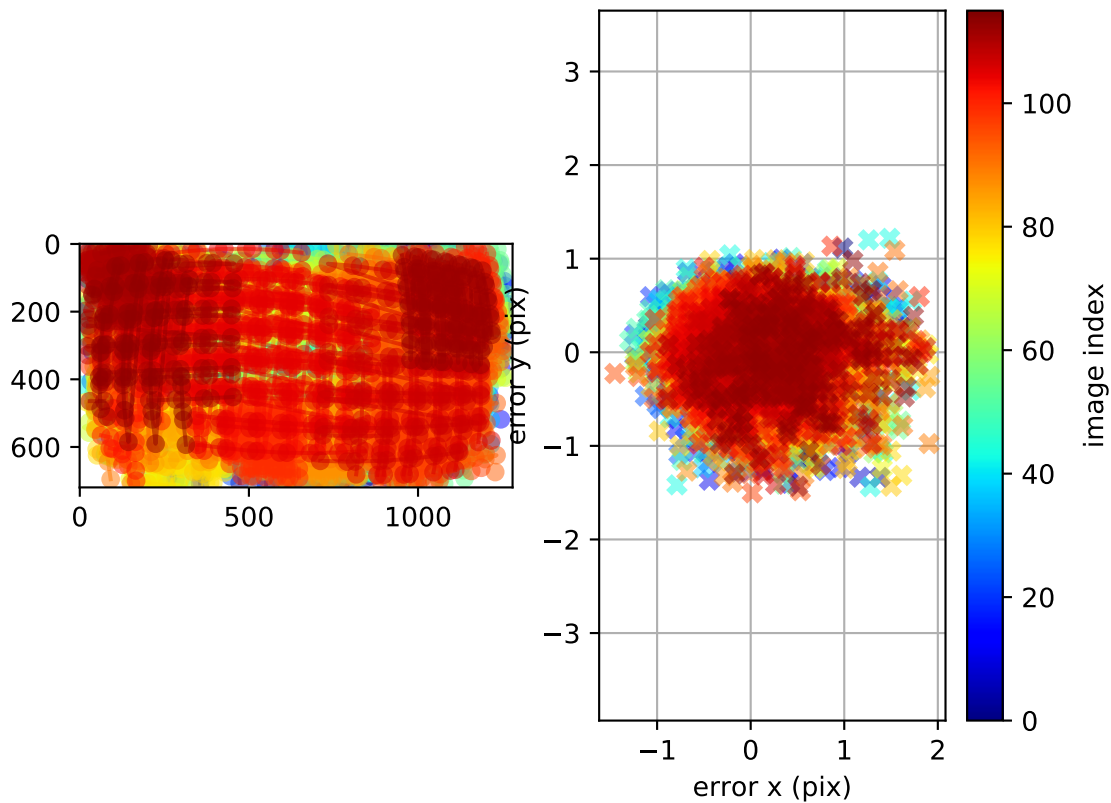
cam1: polar error



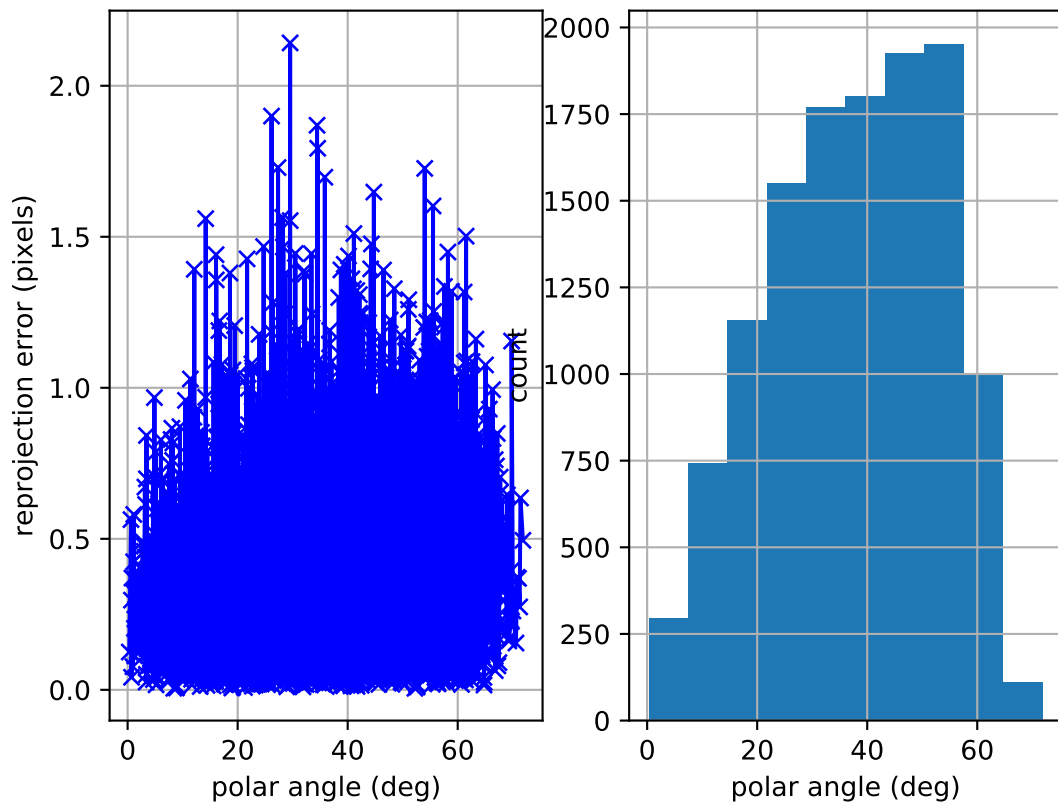
cam1: azimuthal error



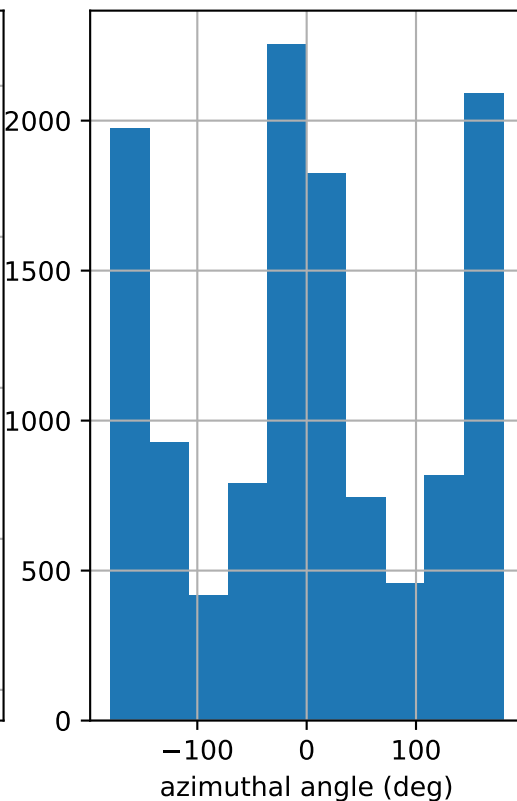
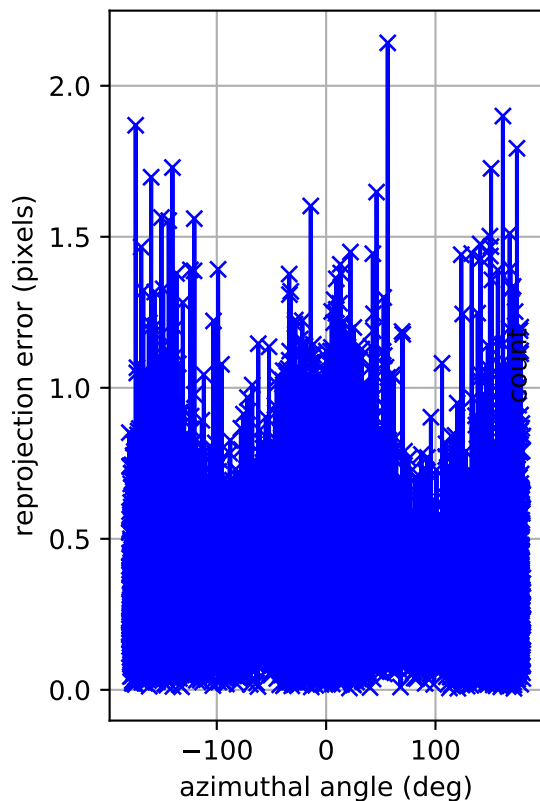
cam1: reprojection errors



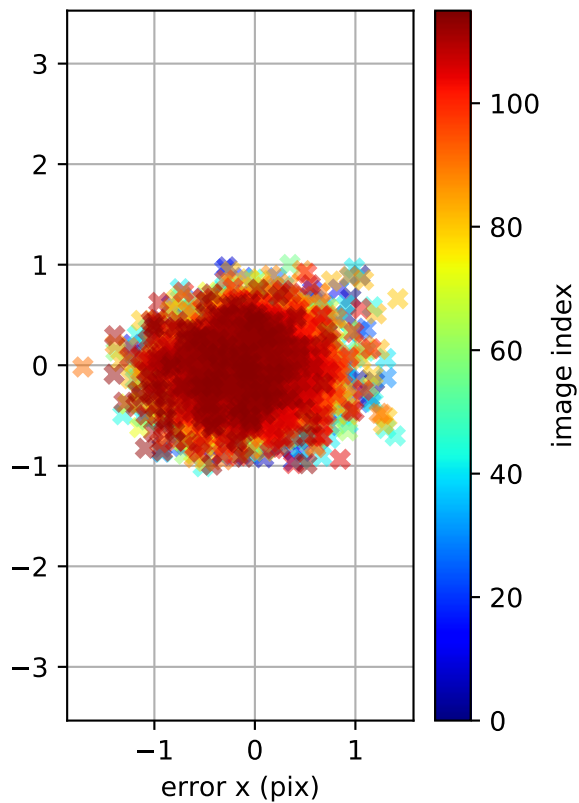
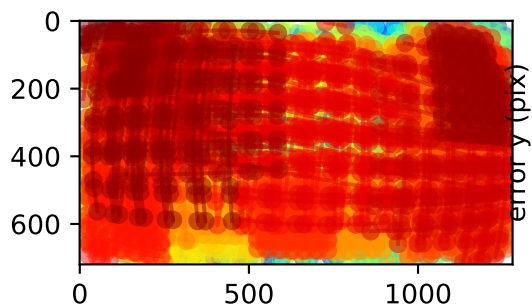
cam2: polar error



cam2: azimuthal error



cam2: reprojection errors



Location of removed outlier corners

