

Calibration results

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Camera-system parameters:

cam0 (/color_left):

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

distortion: [0.02905145 0.09266618 -0.00498243 -0.00091654] +- [0.02996725 0.08263133 0.00334483 0.00370038]

projection: [547.97513838 549.12456359 300.24727552 260.10100412] +- [0.9778687 1.04544489 0.62320219 3.80565313]

reprojection error: [-0.004144, 0.000315] +- [0.470887, 0.372410]

cam1 (/color_right):

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

distortion: [0.04826288 0.02030143 -0.00120781 0.00070354] +- [0.03222397 0.09630616 0.00361633 0.00406473]

projection: [546.26105362 546.97565994 312.98509496 255.98059939] +- [1.05481832 1.22729178 0.70479503 4.4944752]

reprojection error: [0.004385, -0.000140] +- [0.316141, 0.303811]

baseline T_1_0:

q: [-0.01327811 0.00150296 -0.00035776 0.99991065] +- [0.01077537 0.01280307 0.00133956]

t: [-0.0598839 0.00157525 -0.00432479] +- [0.00846308 0.00321689 0.00324967]

Target configuration

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Type: aprilgrid

Tags:

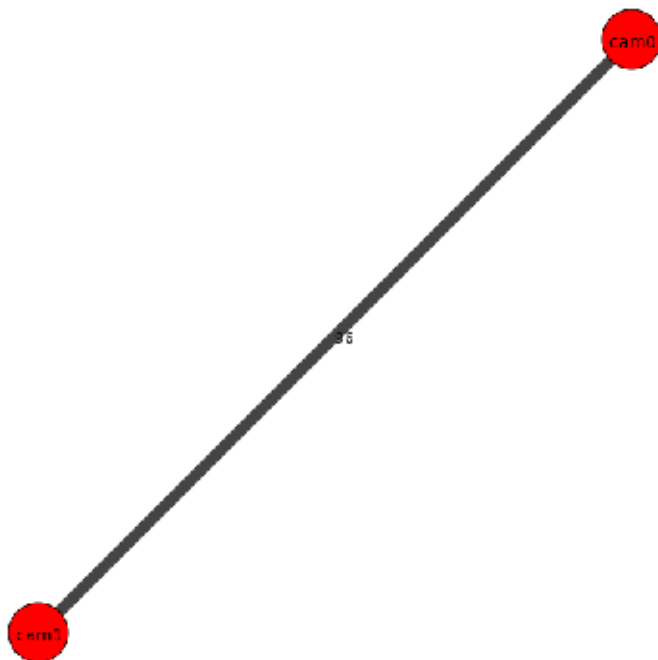
Rows: 6

Cols: 6

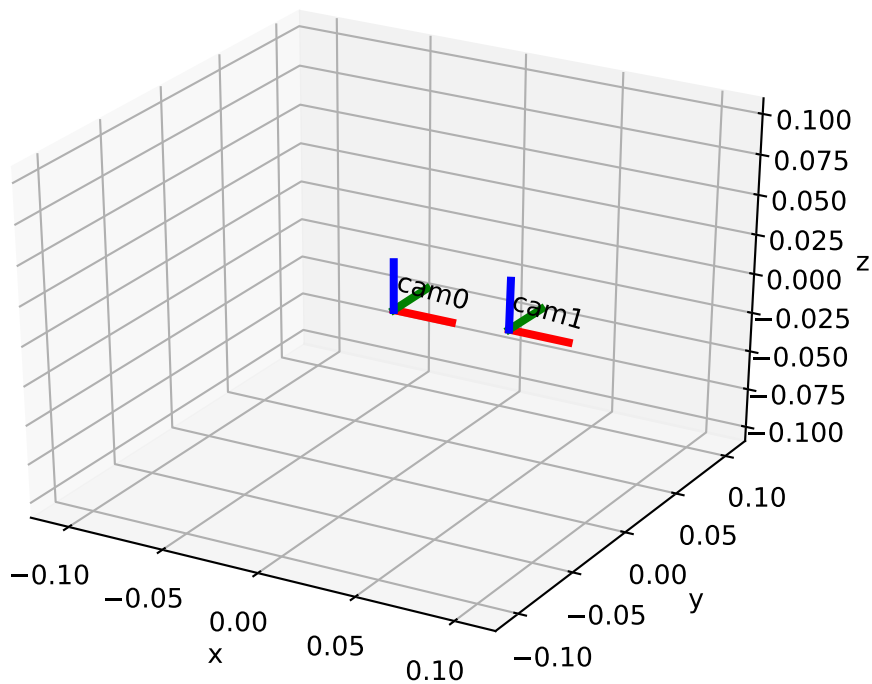
Size: 0.088 [m]

Spacing 0.026399999999999996 [m]

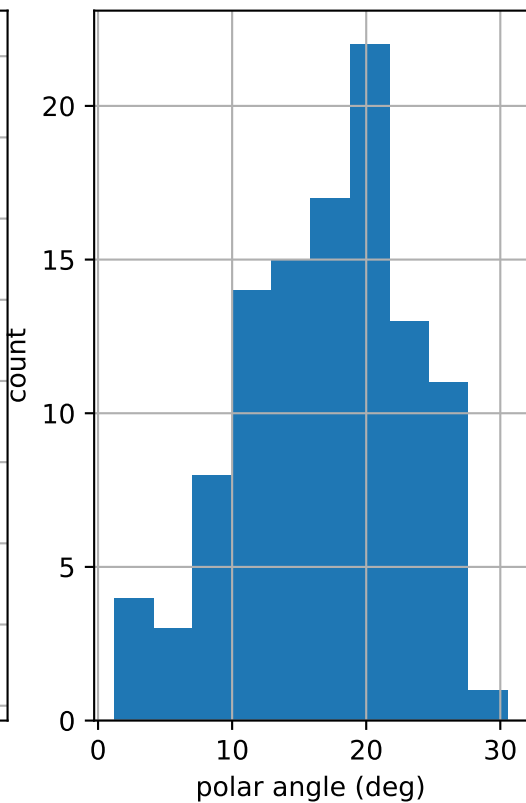
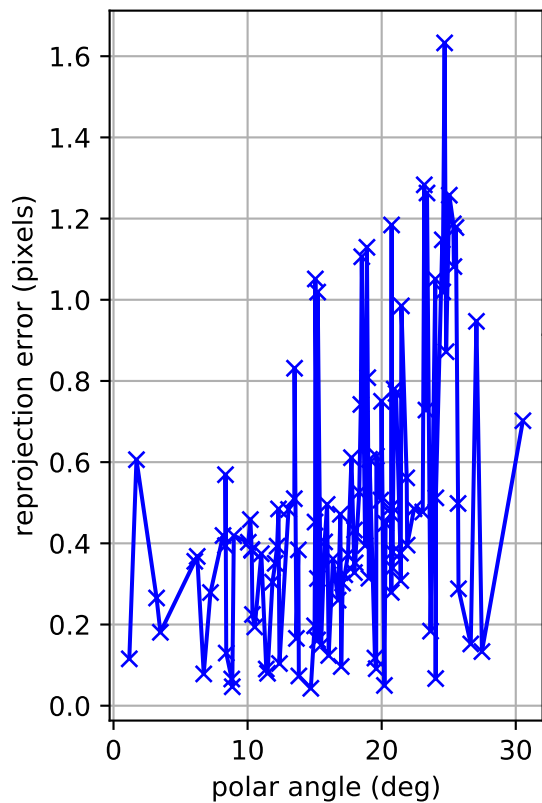
Inter-camera observations graph (edge weight=#mutual obs.)



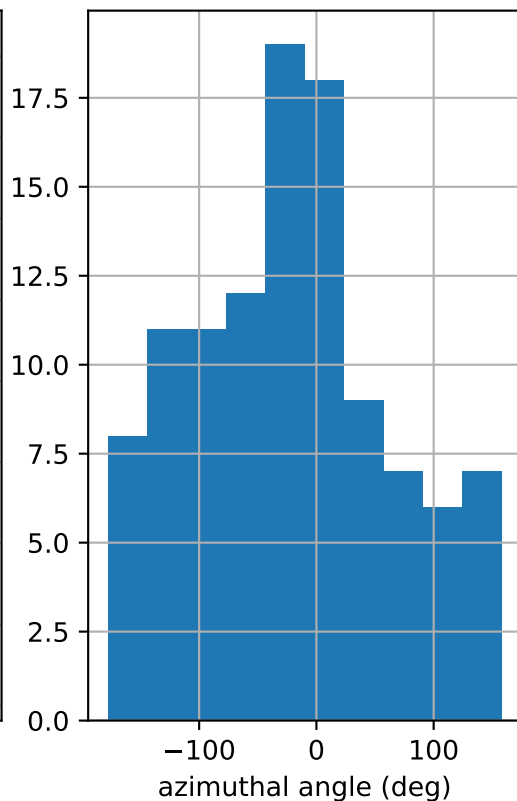
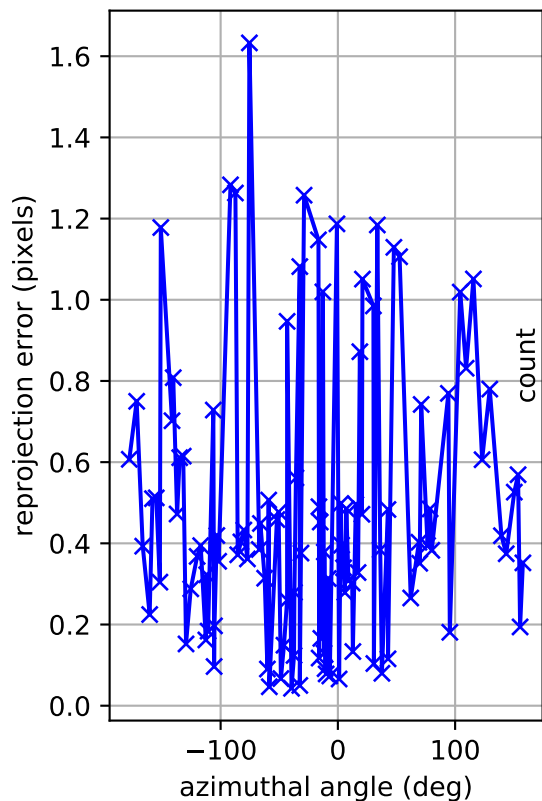
camera system



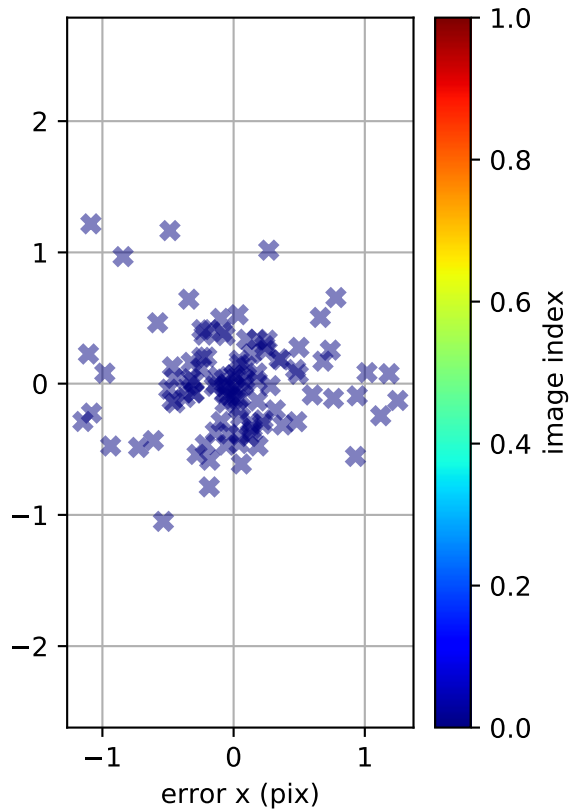
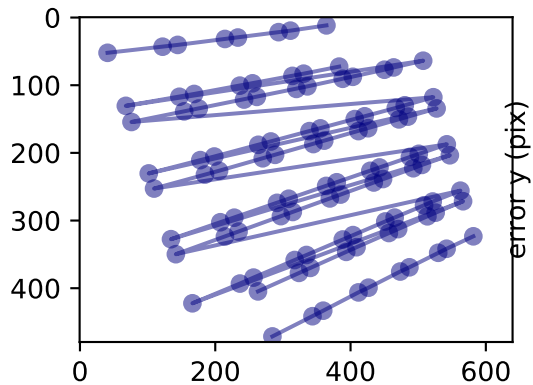
cam0: polar error



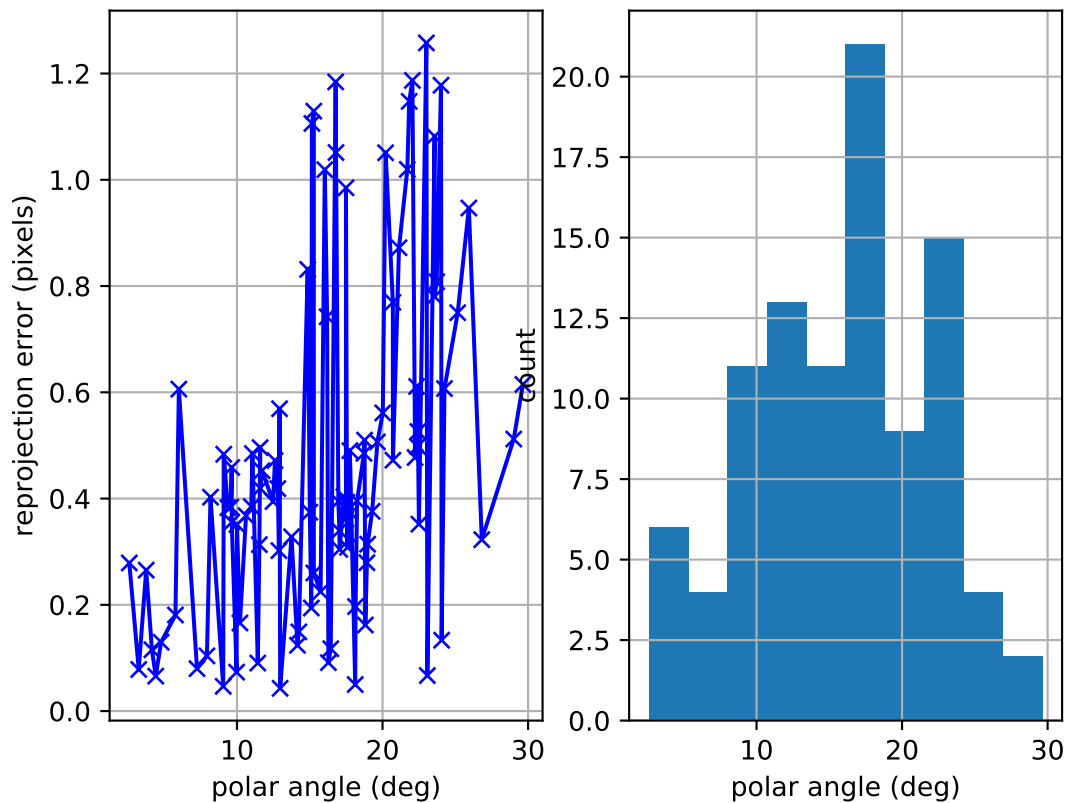
cam0: azimuthal error



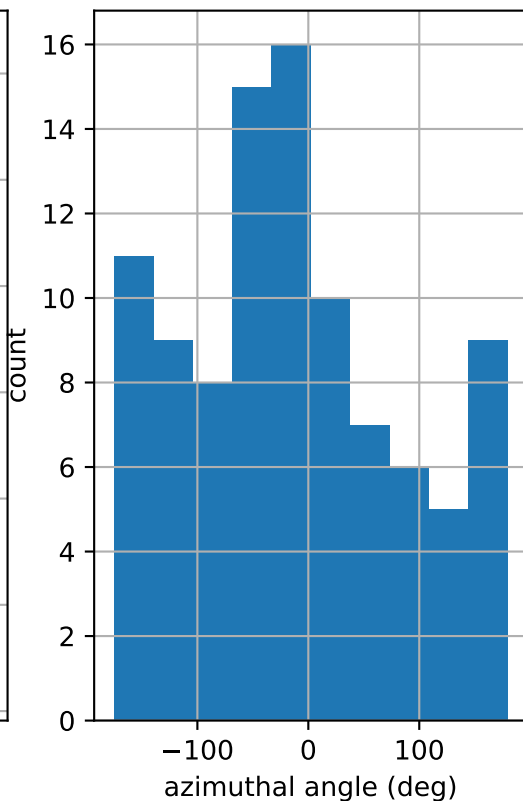
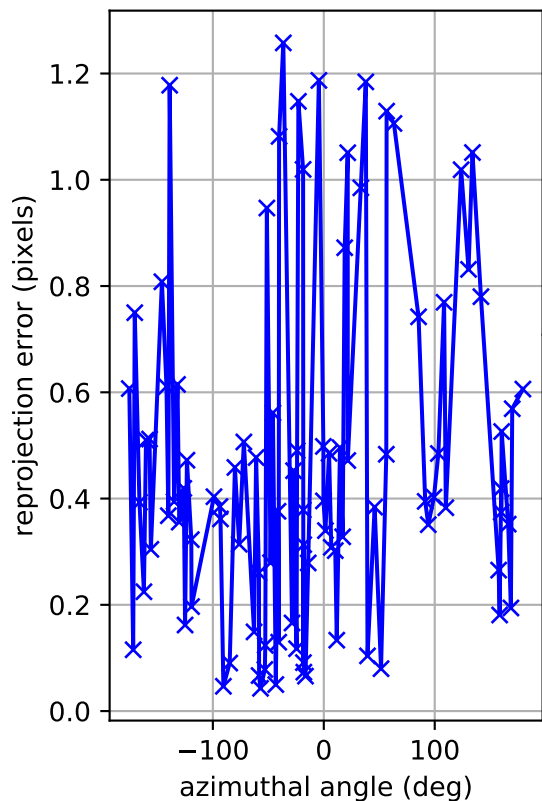
cam0: reprojection errors



cam1: polar error



cam1: azimuthal error



cam1: reprojection errors

