

Calibration results

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Camera-system parameters:

cam0 (/color):

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

distortion: [0.11027052 -0.22697073 -0.00065313 -0.00045016] +- [0.0028587 0.00596285 0.00022459 0.00026041]

projection: [908.14338891 907.70546983 633.88920199 358.70709877] +- [0.15779687 0.14776964 0.32591224 0.20660286]

reprojection error: [0.000241, -0.000046] +- [0.185442, 0.118199]

cam1 (/infra_left):

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

distortion: [-0.0023583 0.0103112 0.00177842 0.00247368] +- [0.00422856 0.01003828 0.00035838 0.00038216]

projection: [426.05899478 426.36633378 433.91420213 235.61365848] +- [0.12134025 0.13242081 0.33531113 0.33459894]

reprojection error: [-0.000090, -0.000144] +- [0.135247, 0.074184]

cam2 (/infra_right):

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

distortion: [-0.00050832 0.00496943 0.00078064 0.00245992] +- [0.00357121 0.00760083 0.00034958 0.00034145]

projection: [427.30151897 427.50541021 434.28844185 234.62295992] +- [0.12242933 0.13681702 0.25755933 0.33688037]

reprojection error: [-0.000266, 0.000025] +- [0.130170, 0.073941]

baseline T_1_0:

q: [-0.0011851 0.00570235 -0.00726679 0.99995664] +- [0.00091972 0.00115314 0.00008415]

t: [-0.01523212 -0.00010121 -0.00281004] +- [0.00013489 0.00013641 0.00037875]

baseline T_2_1:

q: [0.0010249 0.00027928 -0.00000902 0.99999944] +- [0.0011674 0.00026781 0.00011029]

t: [-0.05001288 0.00016976 0.00009694] +- [0.00017502 0.00017442 0.00036071]

Target configuration

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Type: checkerboard

Rows

Count: 8

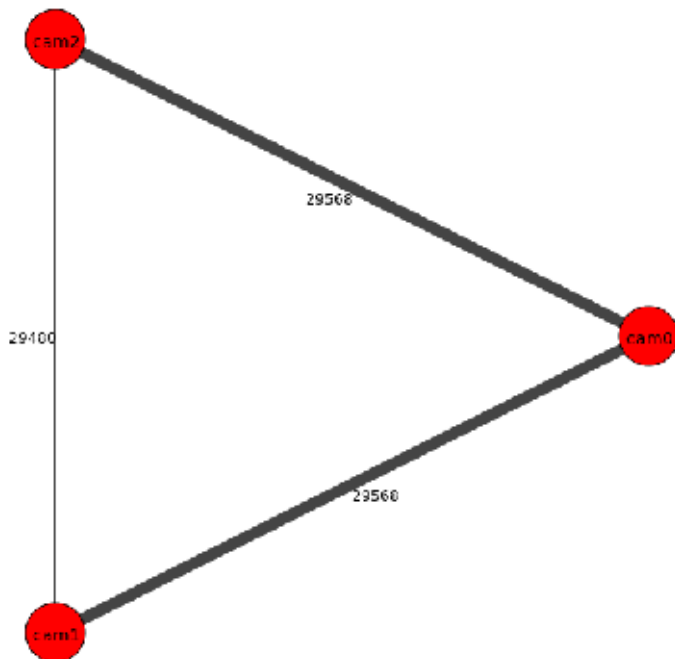
Distance: 0.03 [m]

Cols

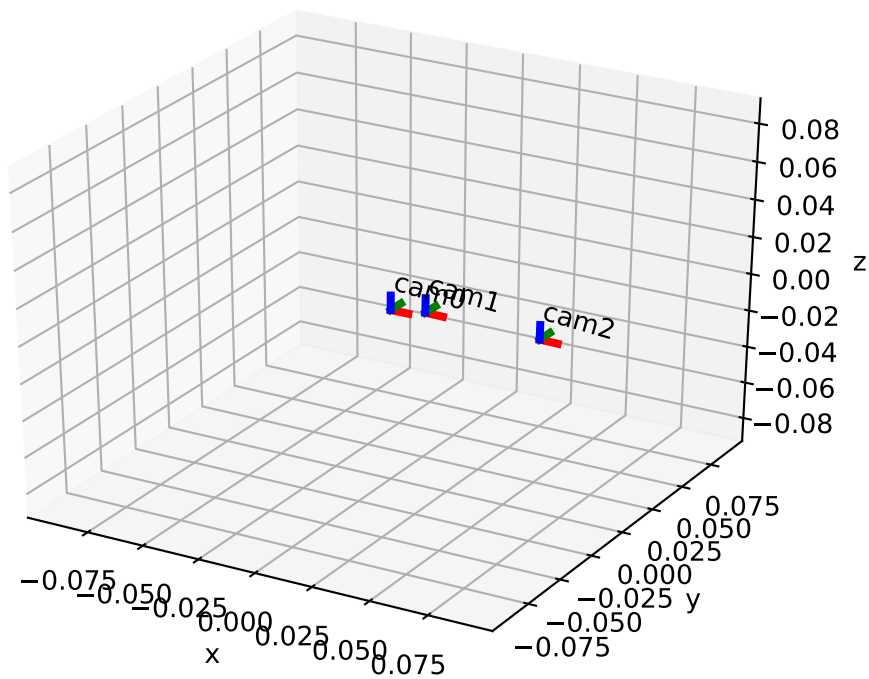
Count: 11

Distance: 0.03 [m]

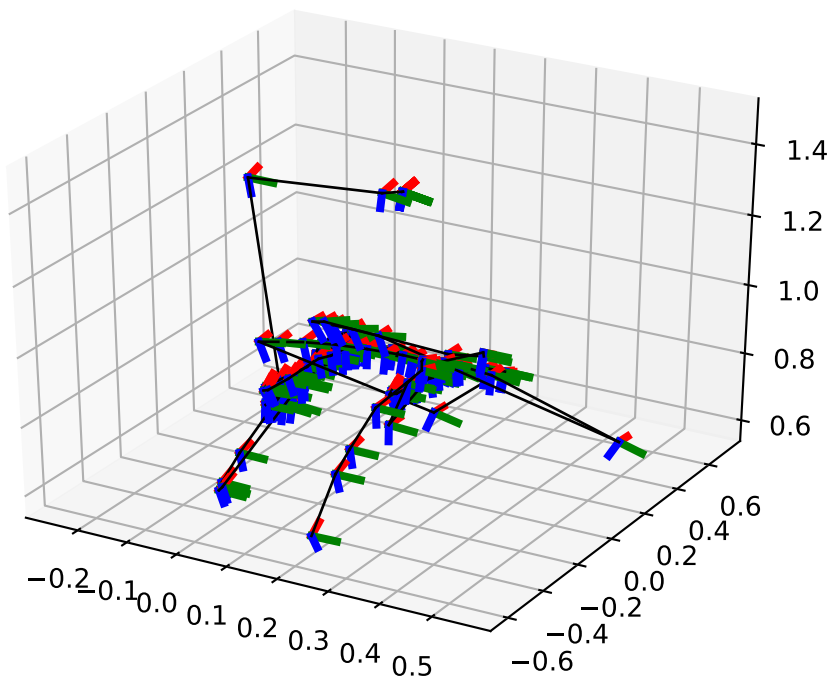
Inter-camera observations graph (edge weight=#mutual obs.)



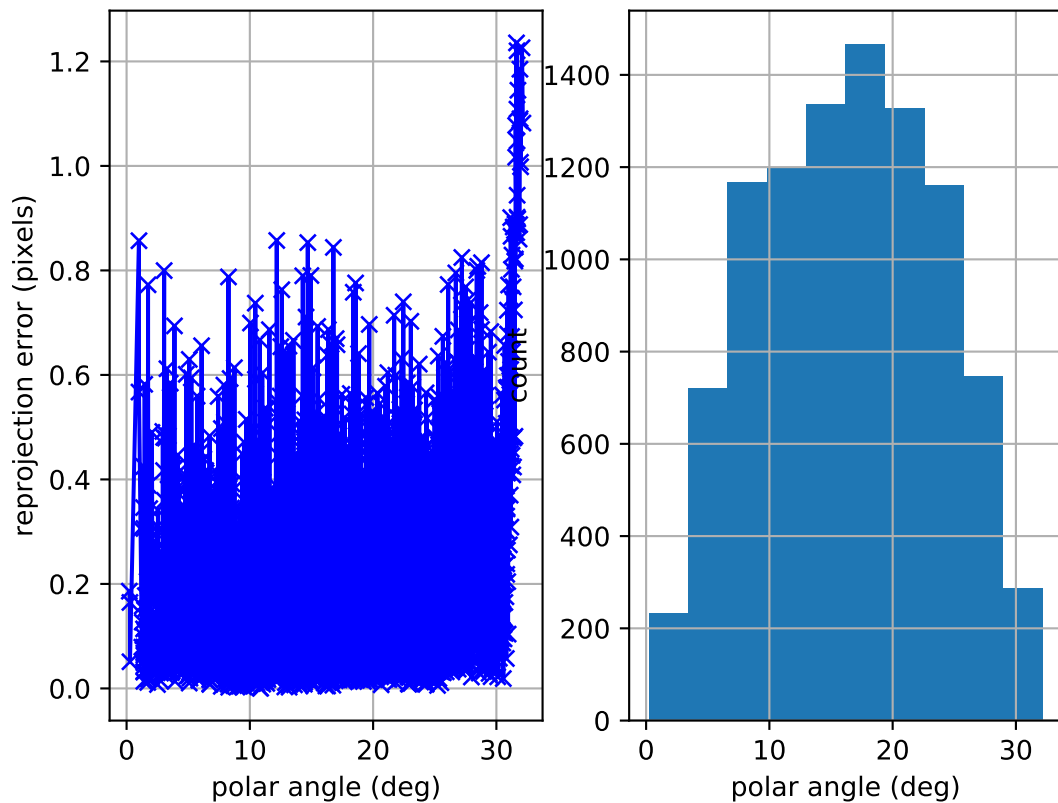
camera system



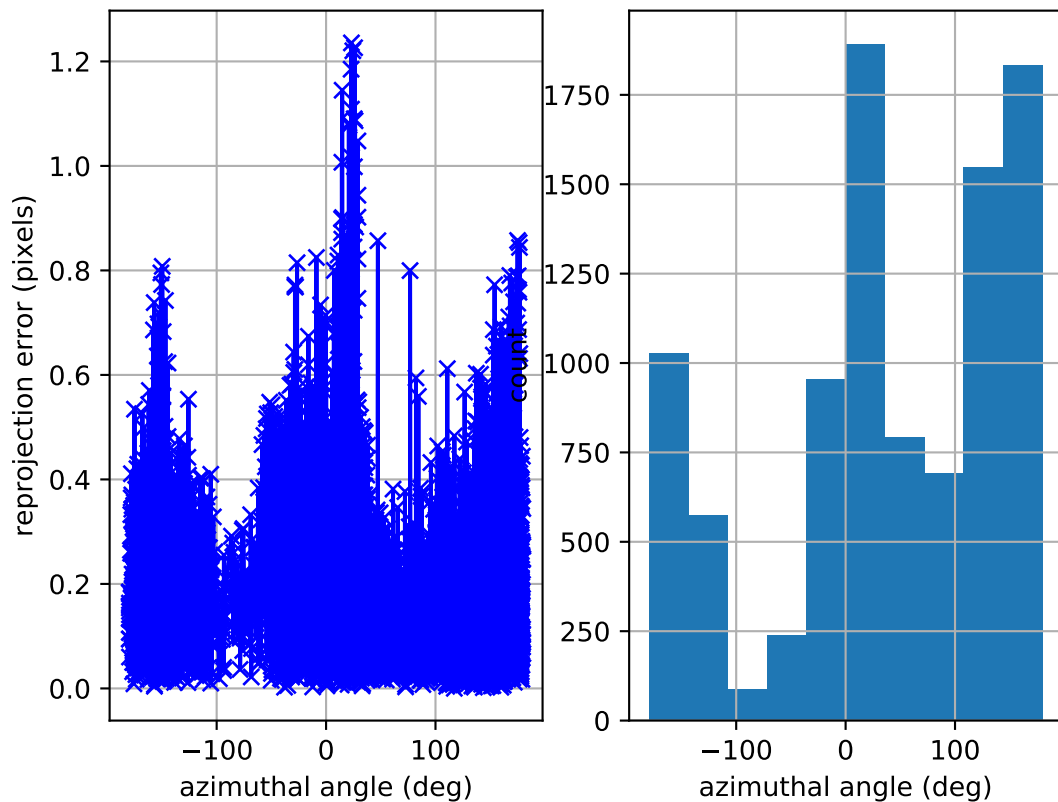
cam0: estimated poses



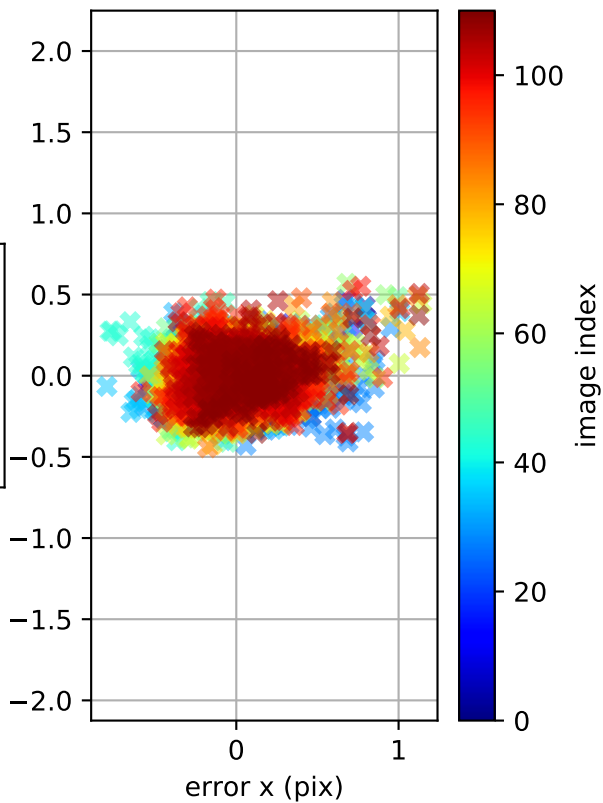
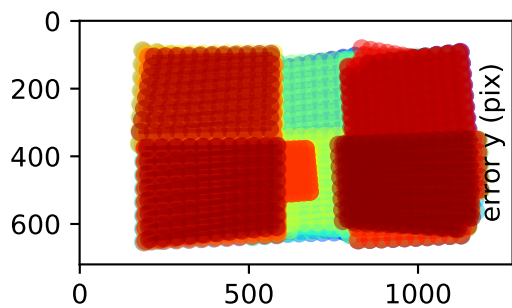
cam0: polar error



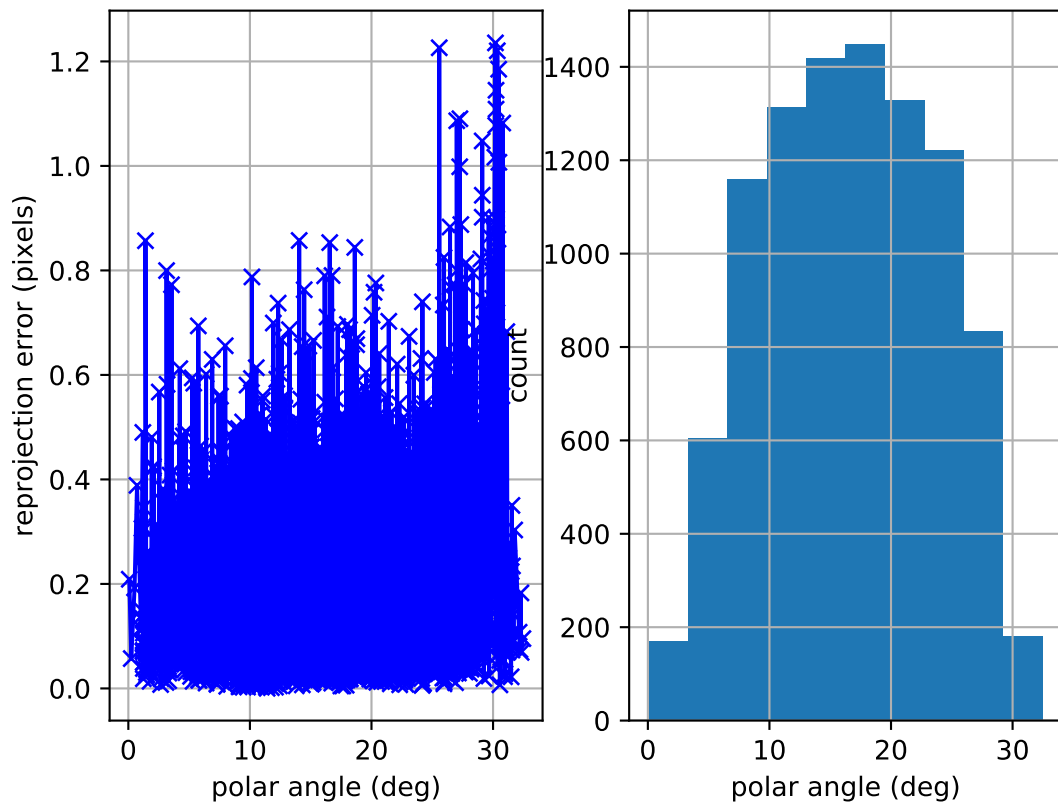
cam0: azimuthal error



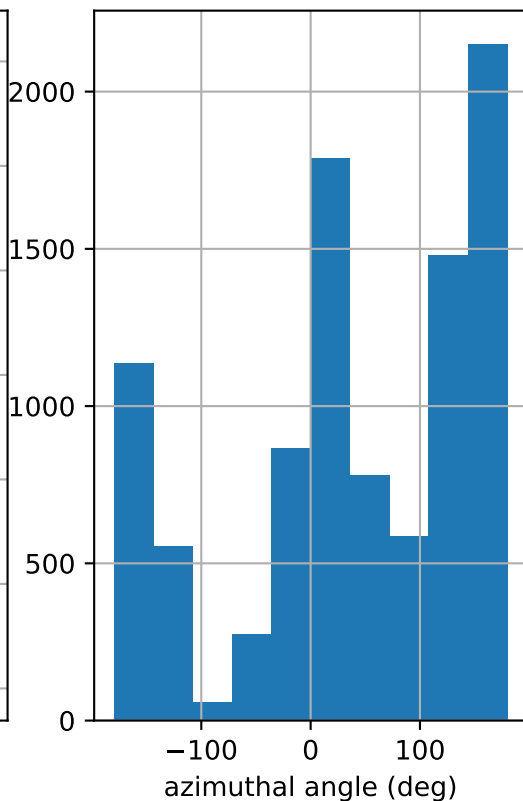
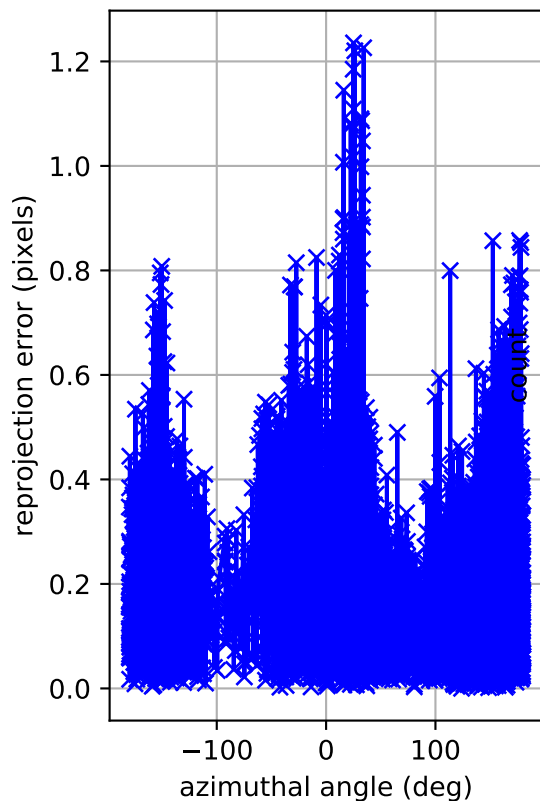
cam0: reprojection errors



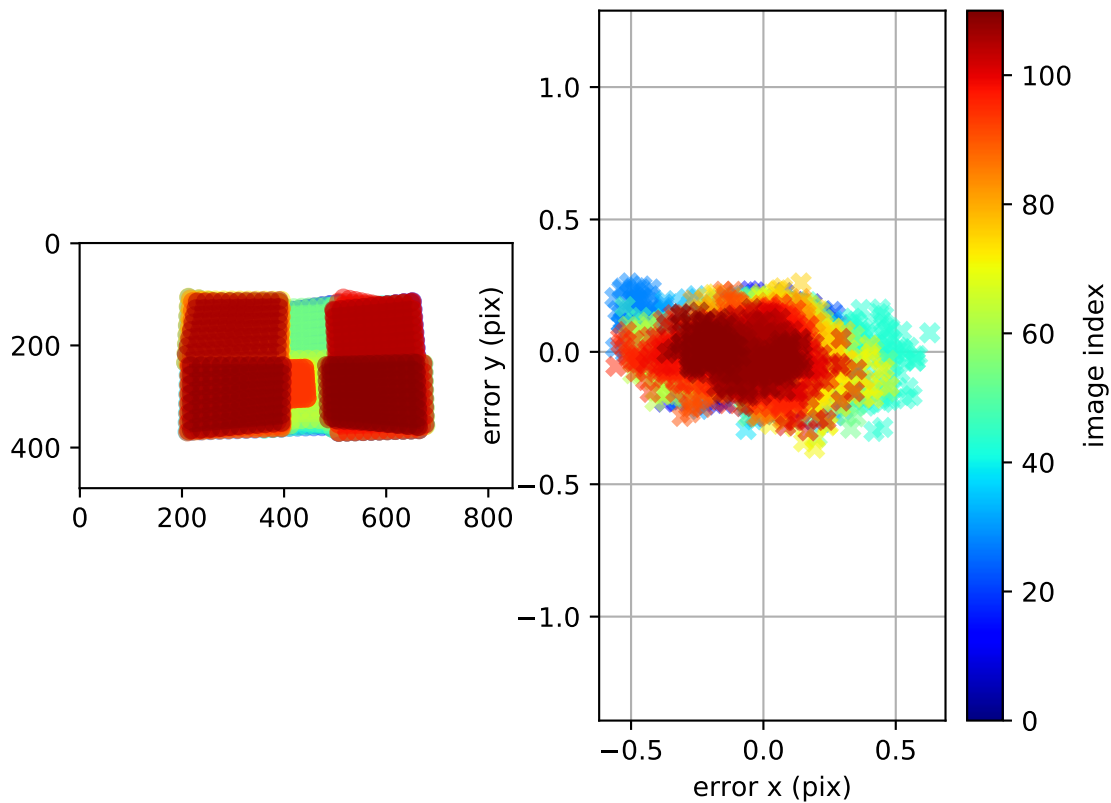
cam1: polar error



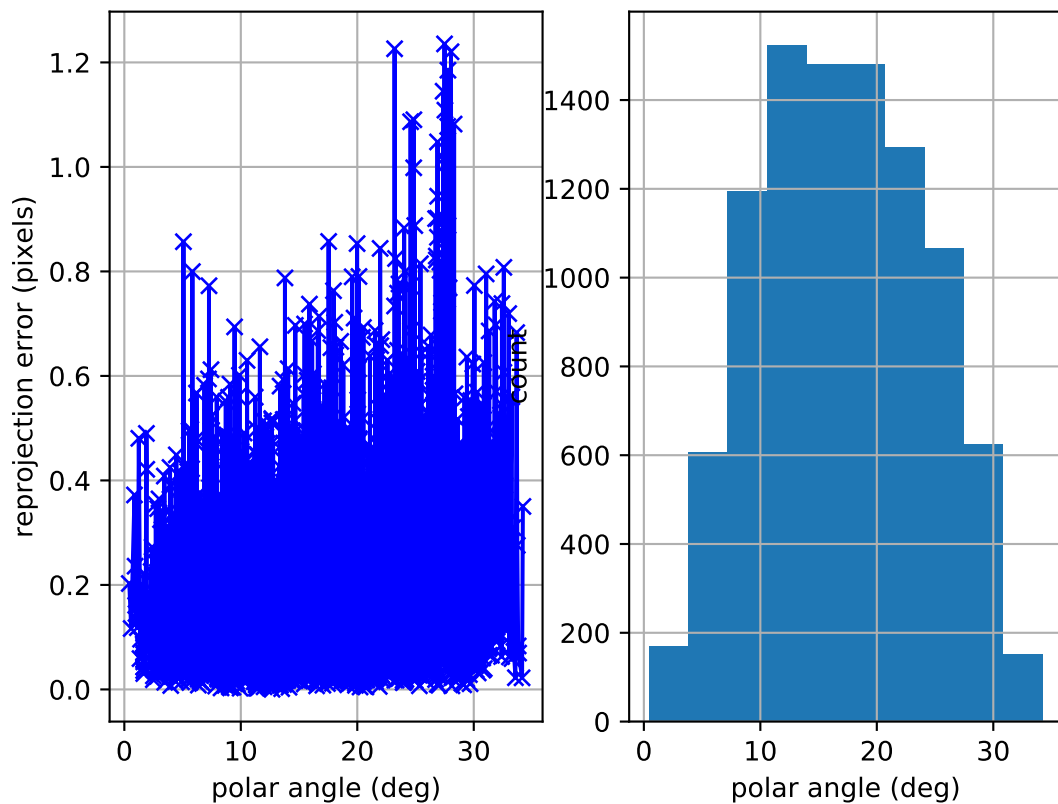
cam1: azimuthal error



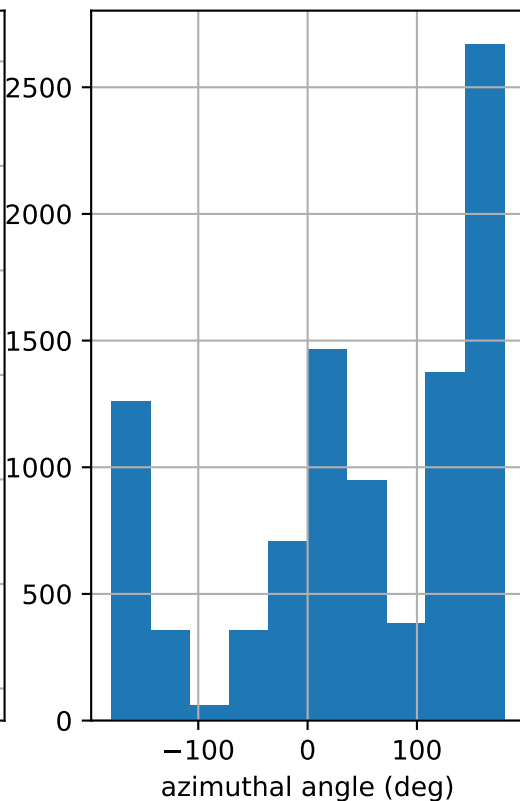
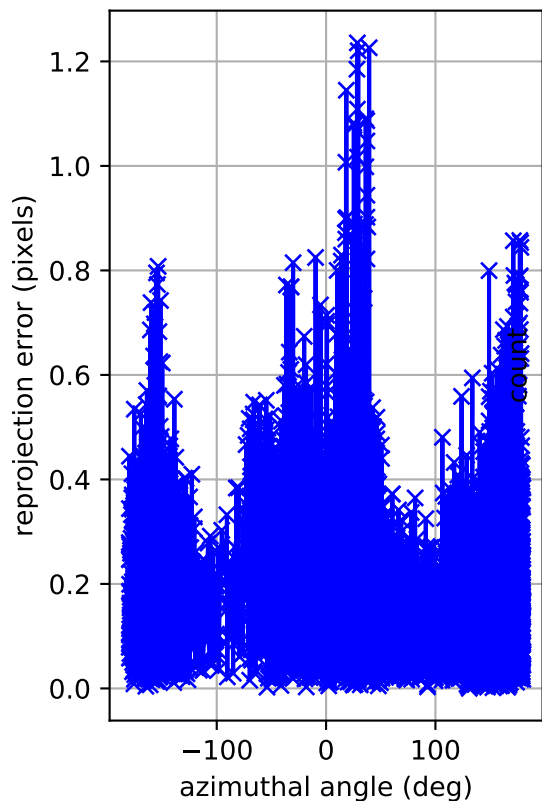
cam1: reprojection errors



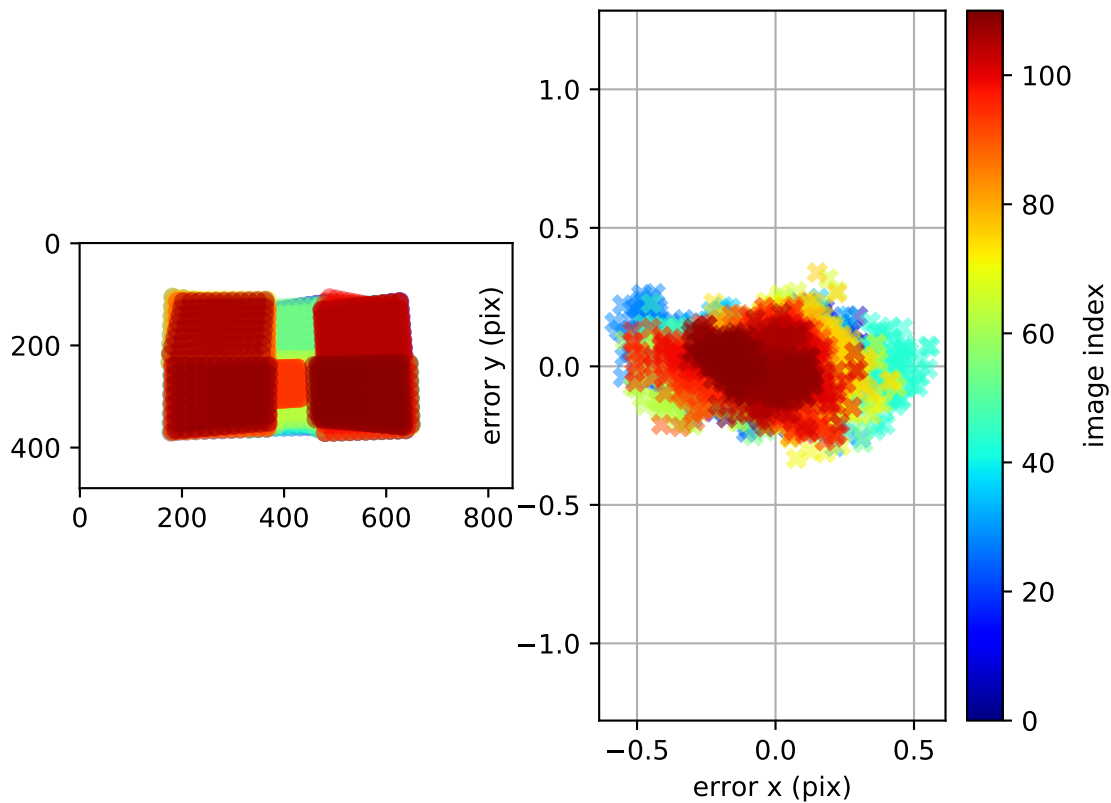
cam2: polar error



cam2: azimuthal error

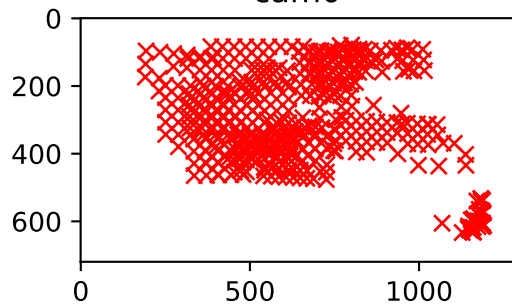


cam2: reprojection errors

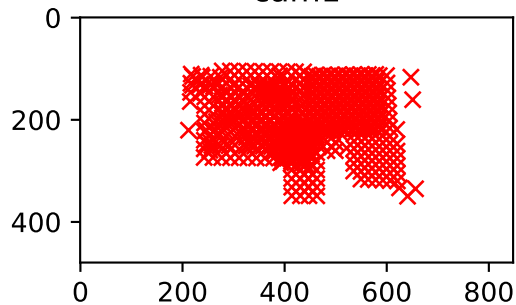


Location of removed outlier corners

cam0



cam1



cam2

