

Calibration results

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Camera-system parameters:

cam0 (/infra_left):

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

distortion: [0.0037286 -0.00250214 0.00011869 -0.00028682] +- [0.00542435 0.01157253 0.00085636 0.00055499]

projection: [424.01734016 424.47875967 430.06184201 232.65769661] +- [0.49014918 0.49341811 0.45782514 1.37206642]

reprojection error: [-0.000000, -0.000003] +- [0.028111, 0.031545]

cam1 (/infra_right):

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

distortion: [0.00506107 -0.00651022 -0.00007373 -0.00055775] +- [0.00474784 0.00912914 0.00084969 0.00056741]

projection: [425.03819174 425.50686368 430.08699131 232.80007843] +- [0.48083841 0.48263922 0.46968611 1.39306238]

reprojection error: [-0.000003, -0.000003] +- [0.028035, 0.032270]

baseline T_1_0:

q: [-0.00026159 -0.00009477 0.00003951 0.99999996] +- [0.00126563 0.00206899 0.00014336]

t: [-0.05000568 0.00003301 0.00011871] +- [0.00033804 0.00032331 0.00173031]

Target configuration

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Type: checkerboard

Rows

Count: 8

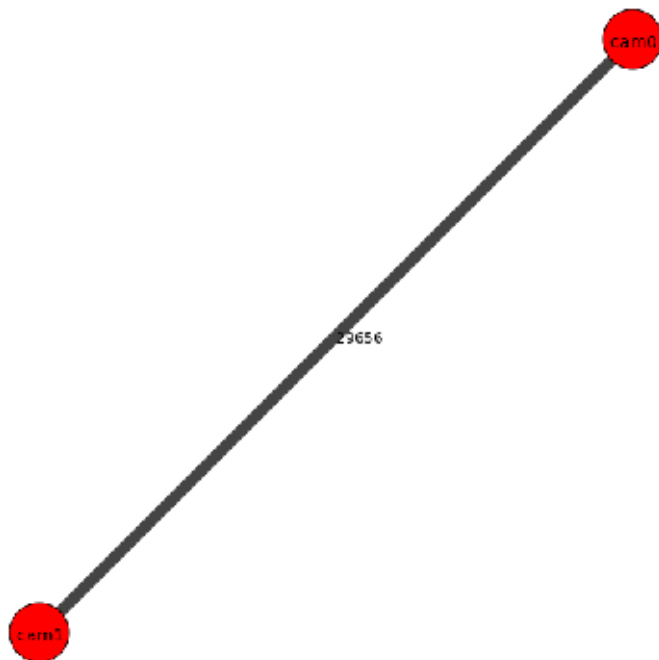
Distance: 0.03 [m]

Cols

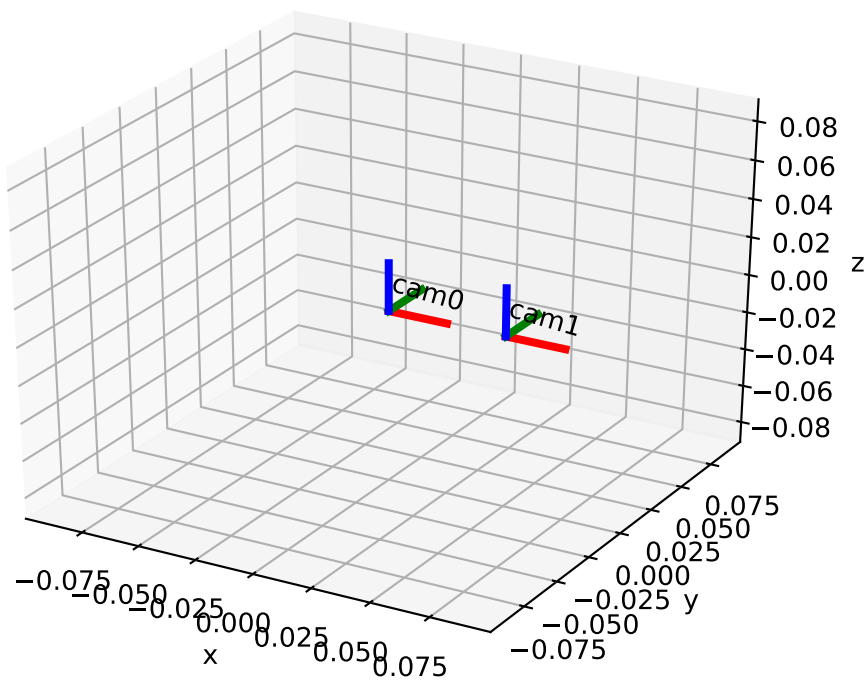
Count: 11

Distance: 0.03 [m]

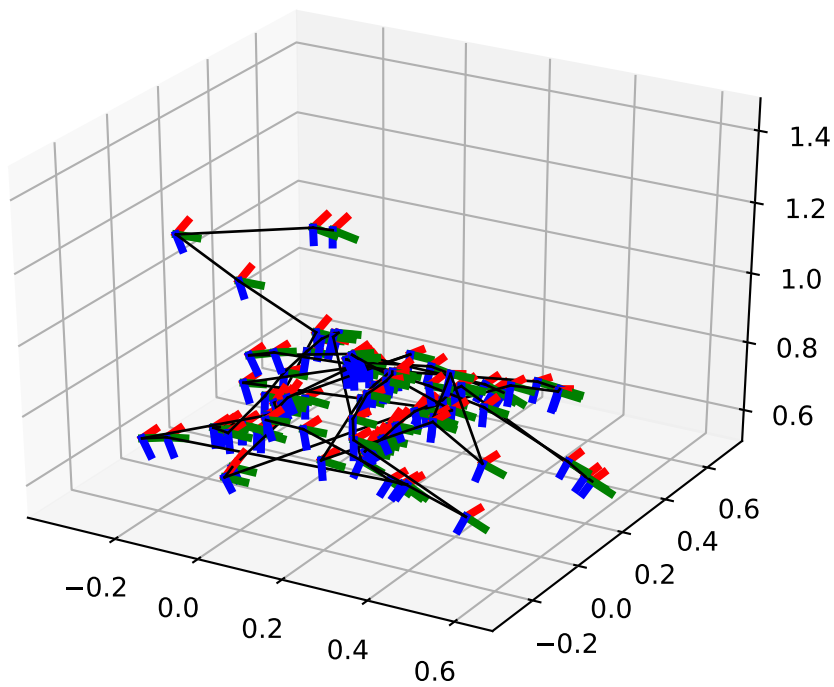
Inter-camera observations graph (edge weight=#mutual obs.)



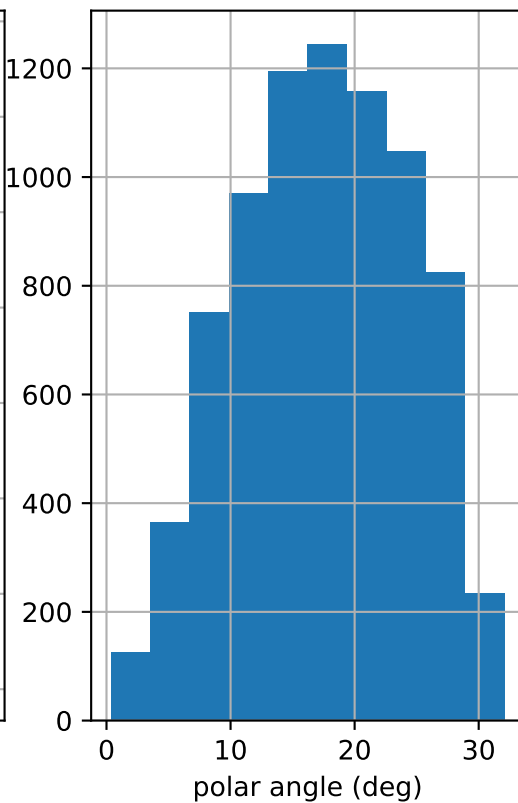
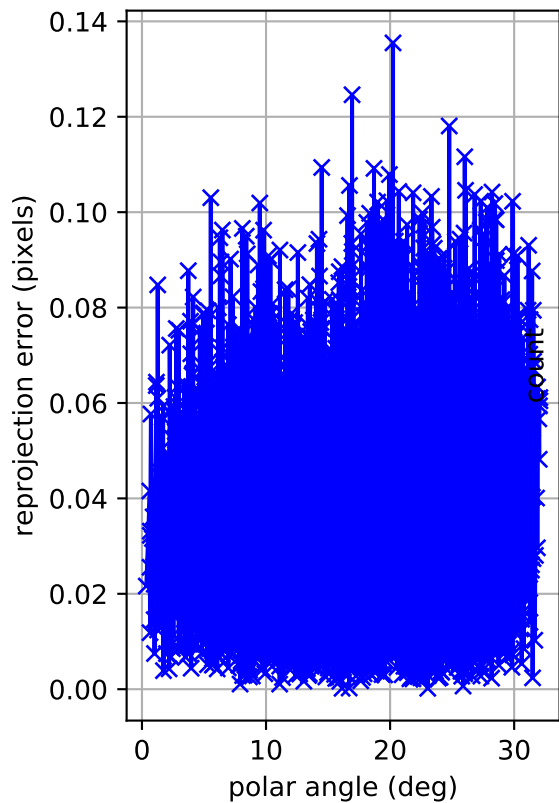
camera system



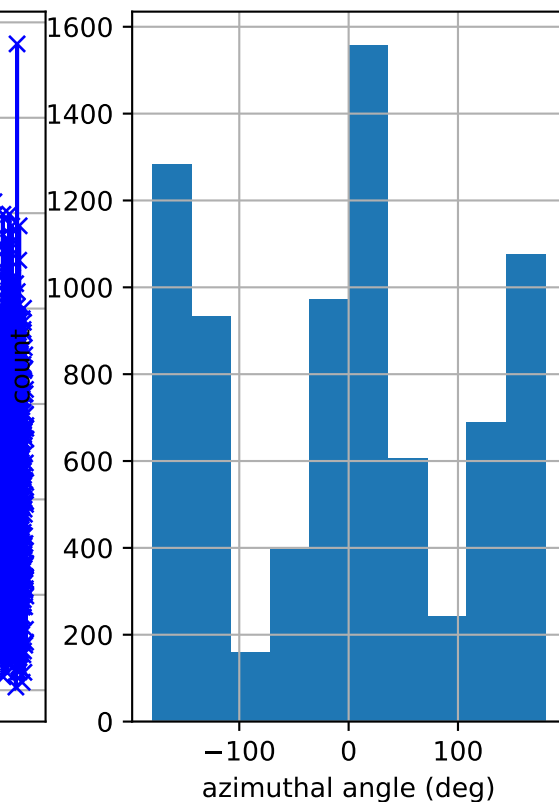
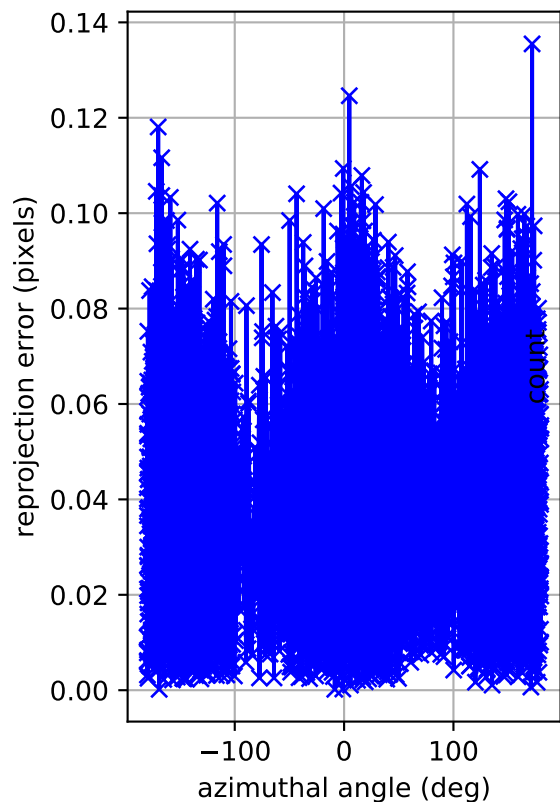
cam0: estimated poses



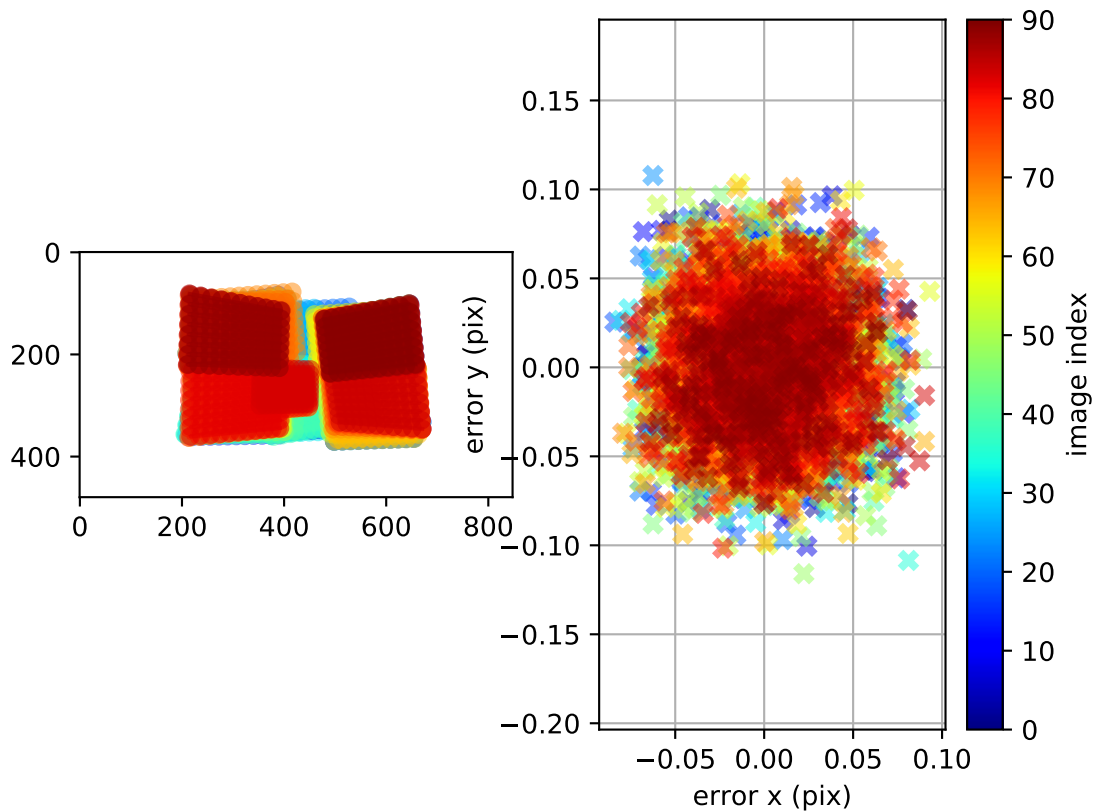
cam0: polar error



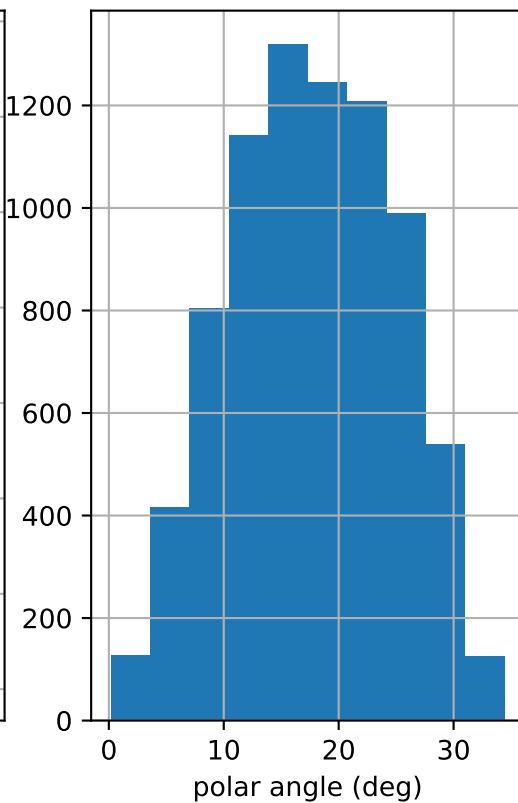
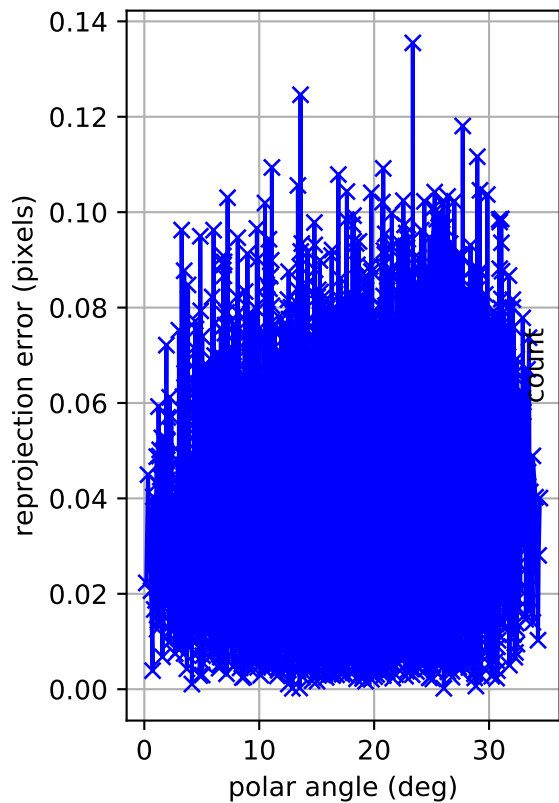
cam0: azimuthal error



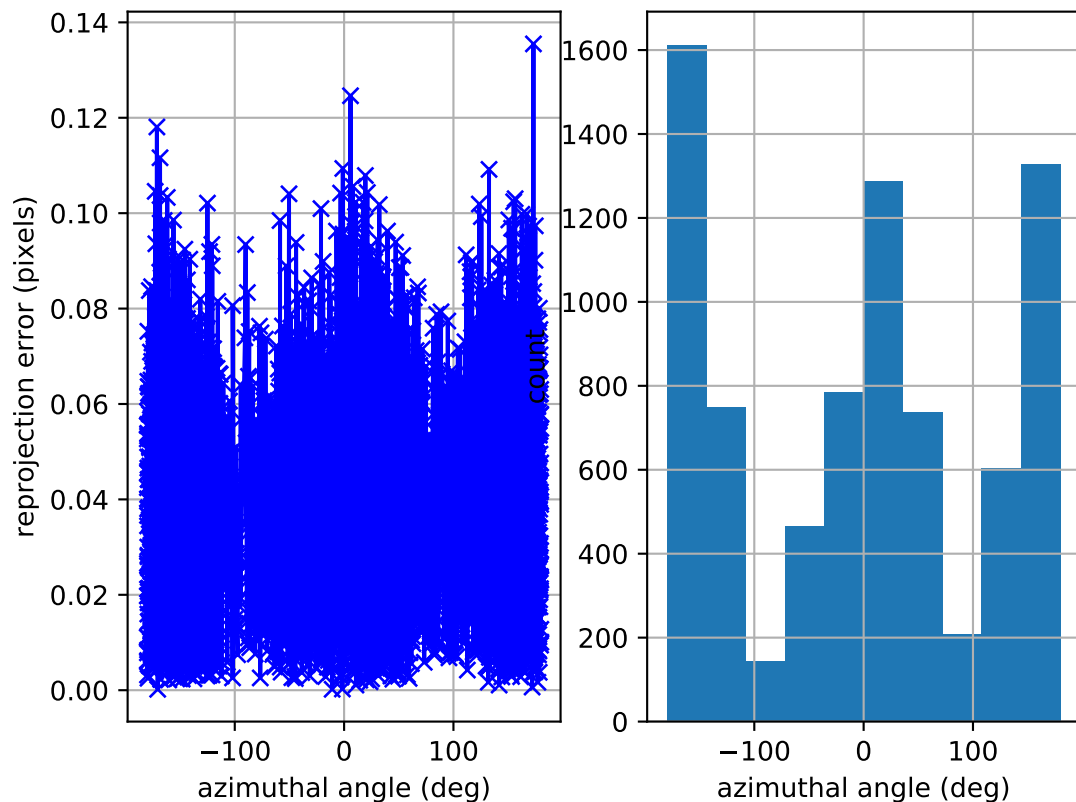
cam0: reprojection errors



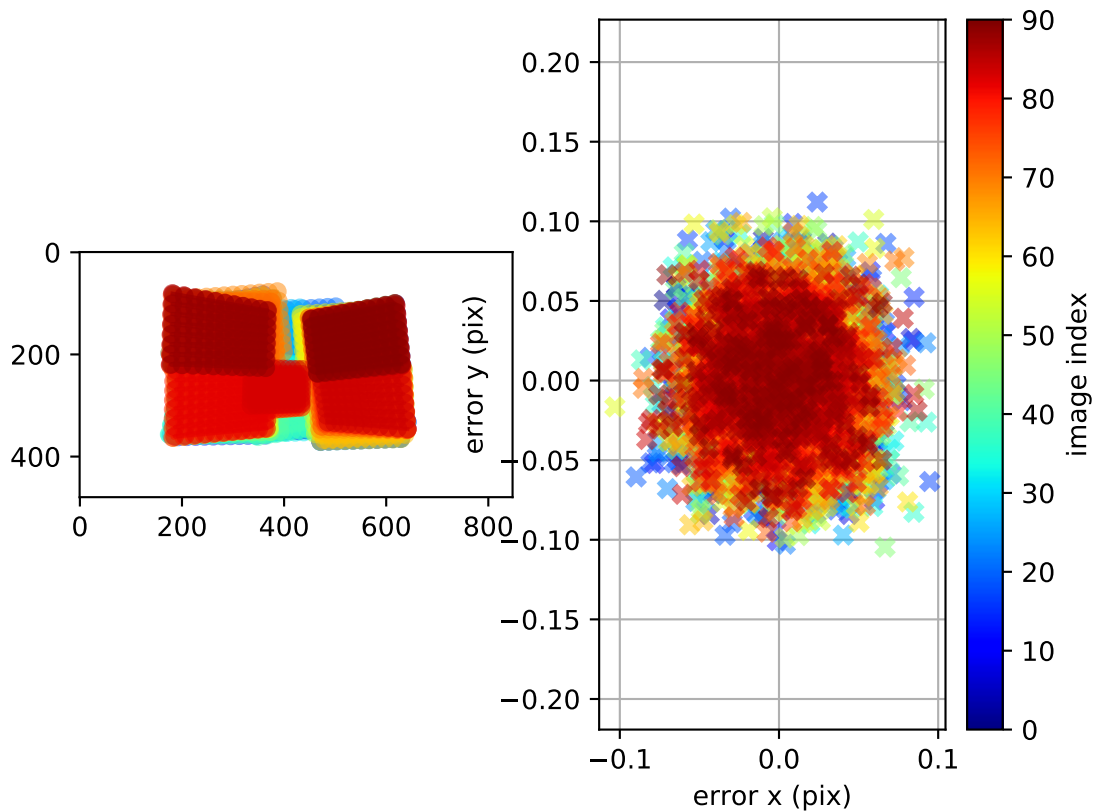
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

