

Calibration results

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Camera-system parameters:

cam0 (/ifo001/camera/infra1/image_rect_raw):

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

distortion: [0.00005483 -0.00004385 -0.00020333 0.00016573] +- [0.0007918 0.00065111 0.00019798 0.00024178]

projection: [426.8825036 429.443822 424.99696244 245.66951373] +- [0.60692967 0.59629306 0.45264239 0.40148721]

reprojection error: [0.000007, -0.000000] +- [0.305829, 0.306275]

cam1 (/ifo001/camera/infra2/image_rect_raw):

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

distortion: [0.00053354 -0.00040284 -0.00013349 0.00028899] +- [0.00078416 0.00063738 0.00019845 0.0002395]

projection: [427.78000954 430.34913786 426.59208756 246.4067373] +- [0.60467797 0.59588207 0.45373632 0.40136564]

reprojection error: [-0.000007, 0.000000] +- [0.299792, 0.296767]

baseline T_1_0:

q: [0.0000433 0.00187068 -0.00016026 0.99999824] +- [0.0003751 0.00072011 0.00006153]

t: [-0.05000902 -0.00010629 0.00007991] +- [0.00007519 0.00007439 0.00017435]

Target configuration

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Type: aprilgrid

Tags:

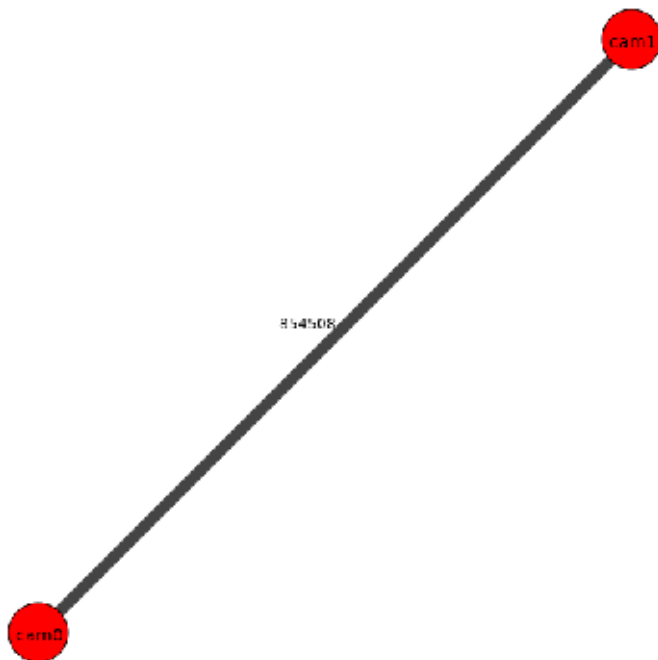
Rows: 6

Cols: 6

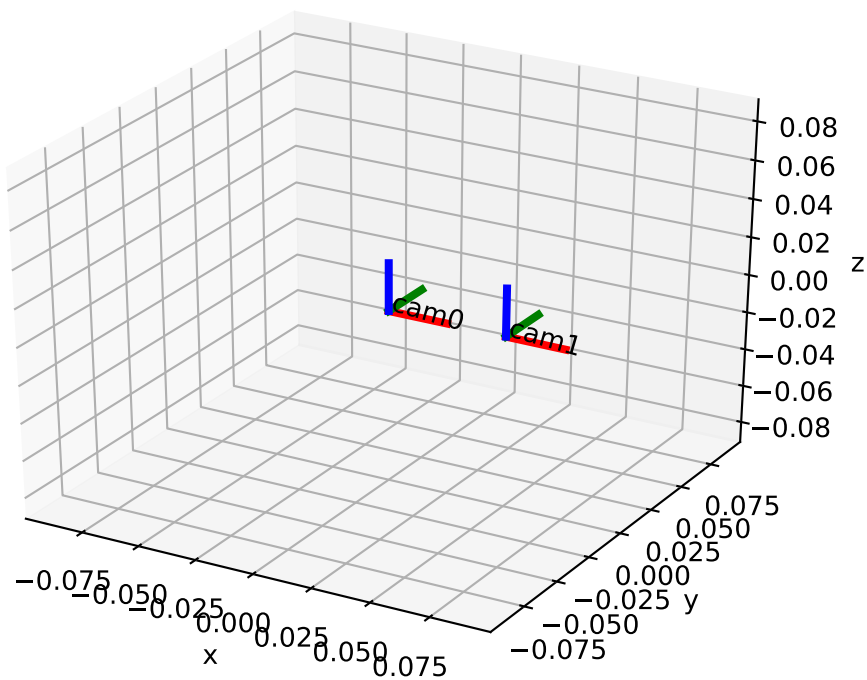
Size: 0.0625 [m]

Spacing 0.01875 [m]

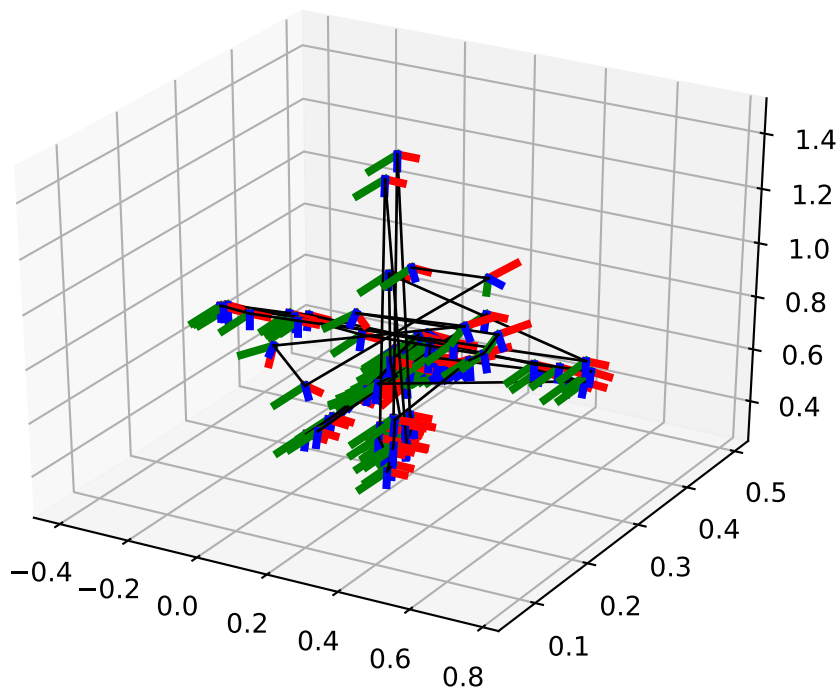
Inter-camera observations graph (edge weight=#mutual obs.)



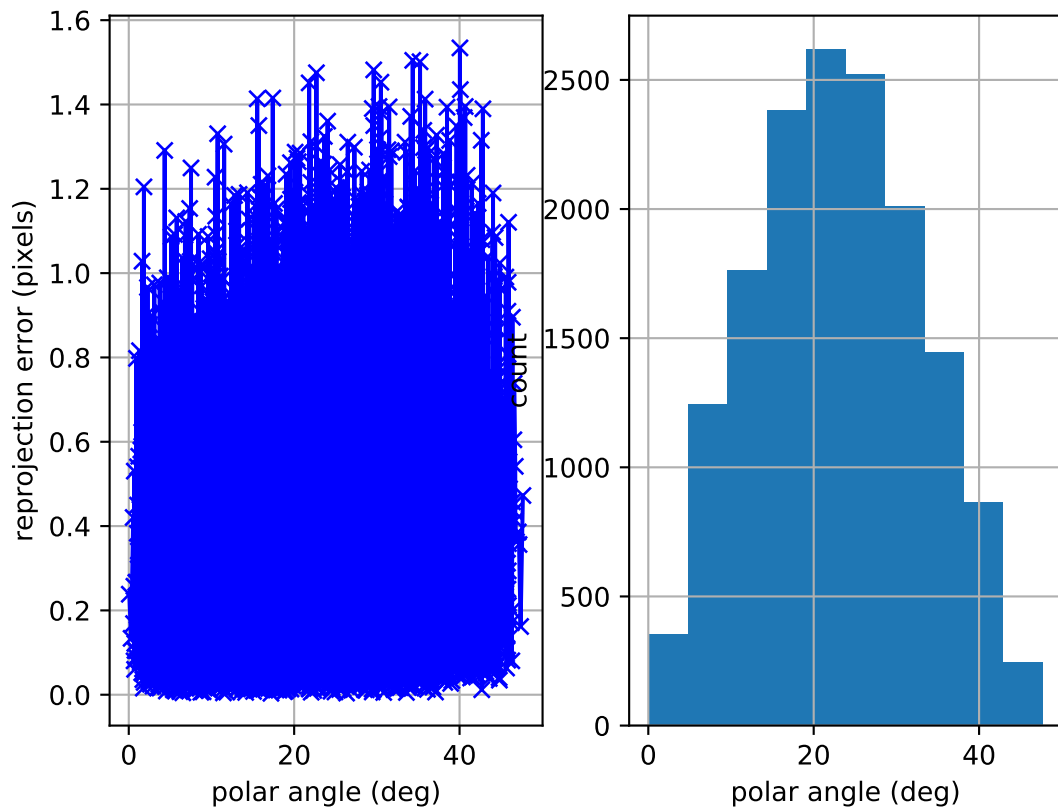
camera system



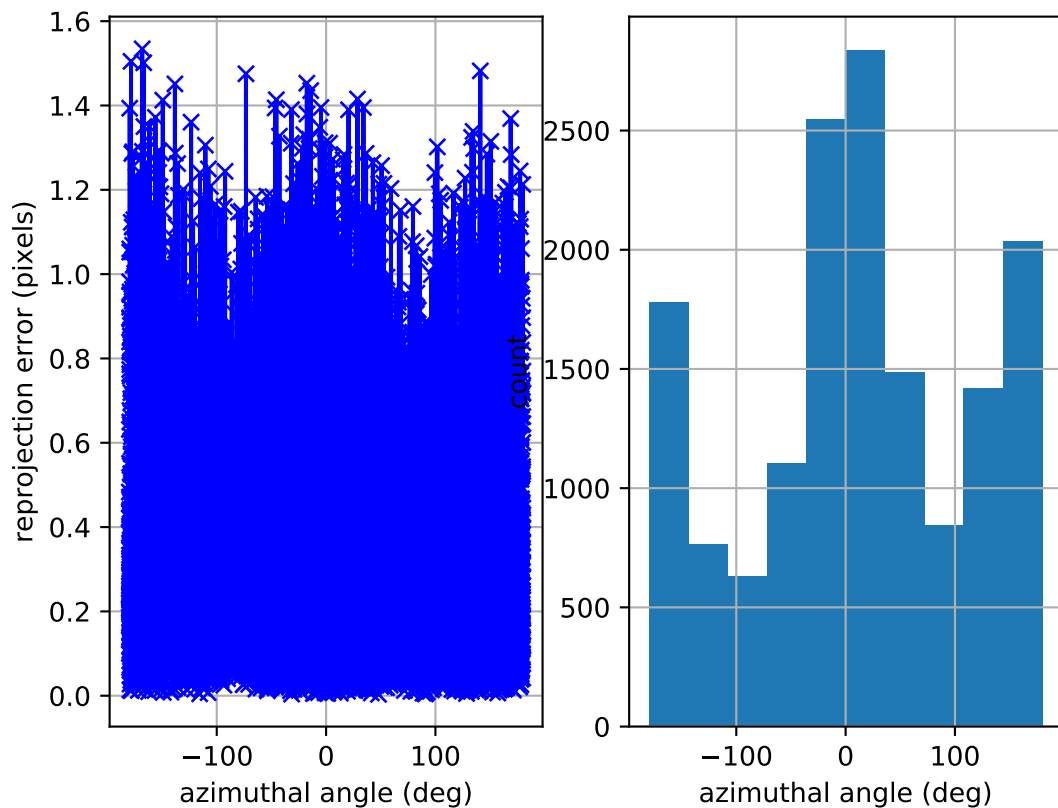
cam0: estimated poses



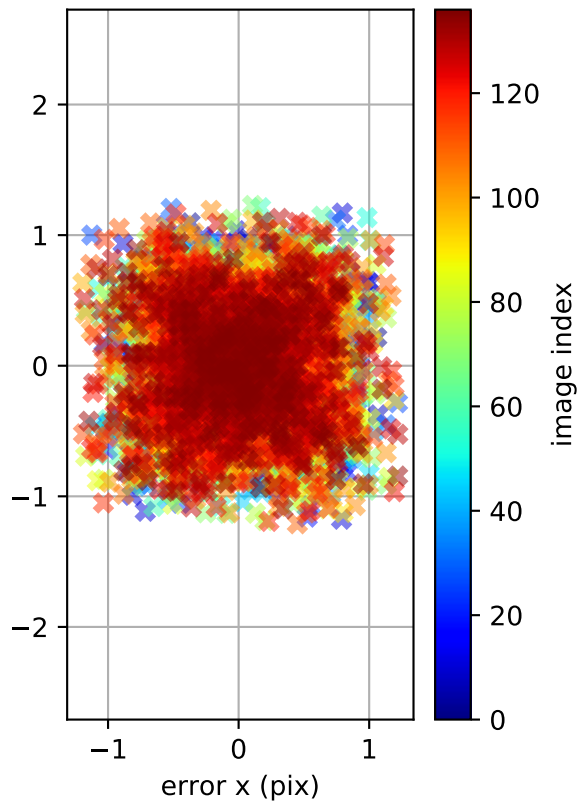
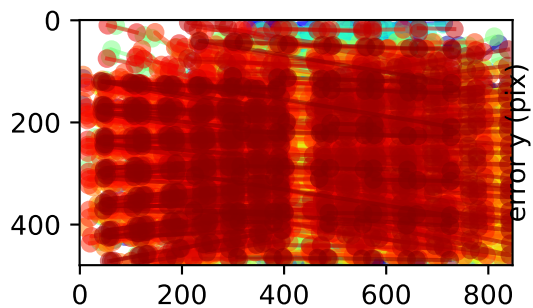
cam0: polar error



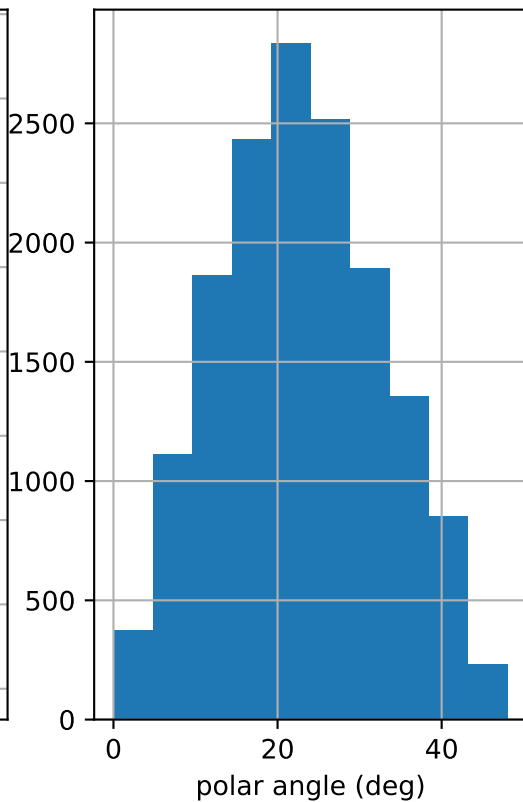
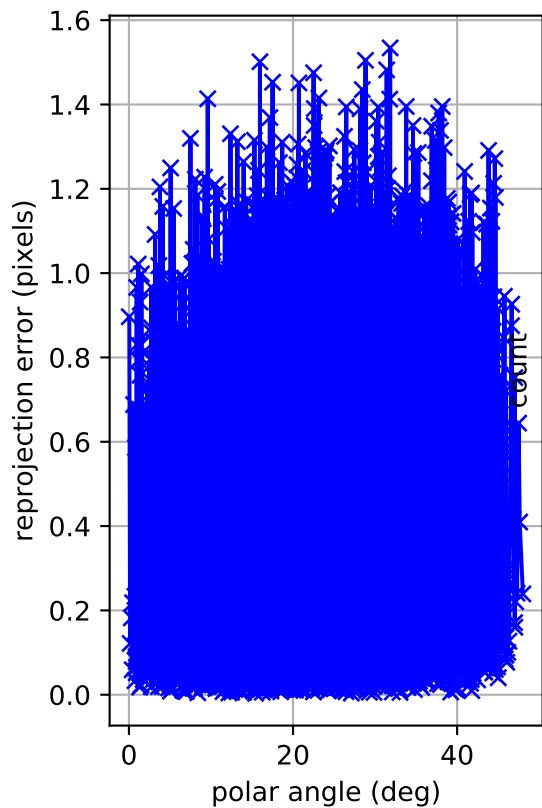
cam0: azimuthal error



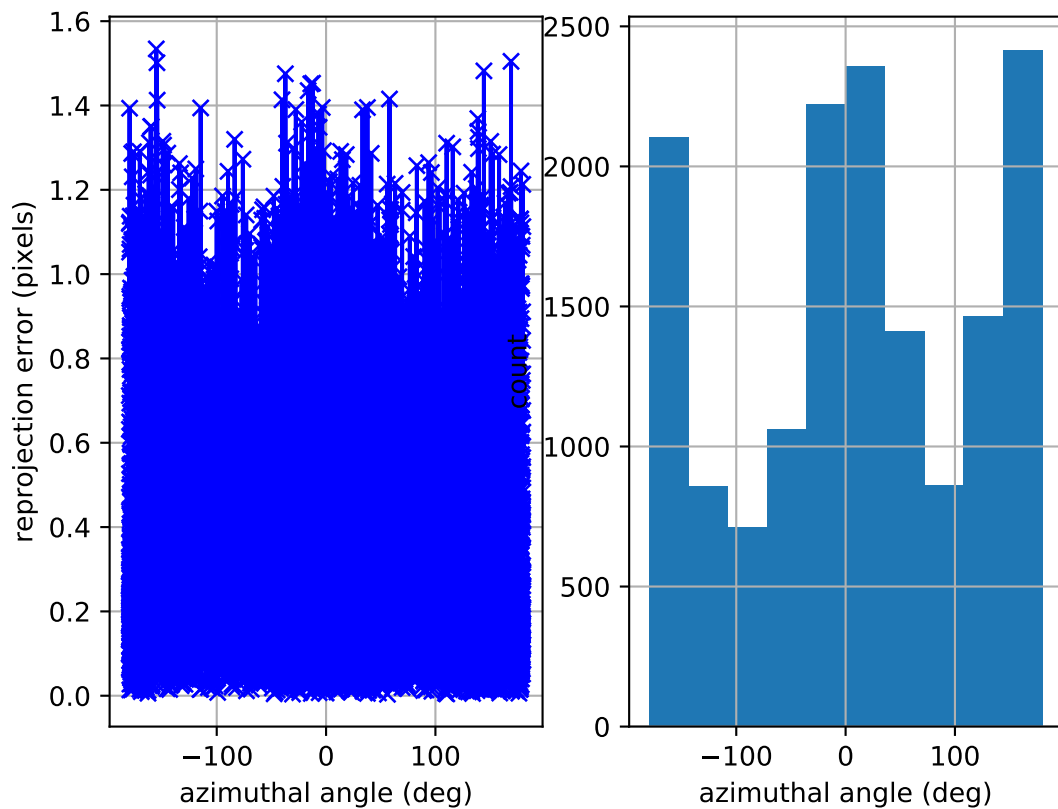
cam0: reprojection errors



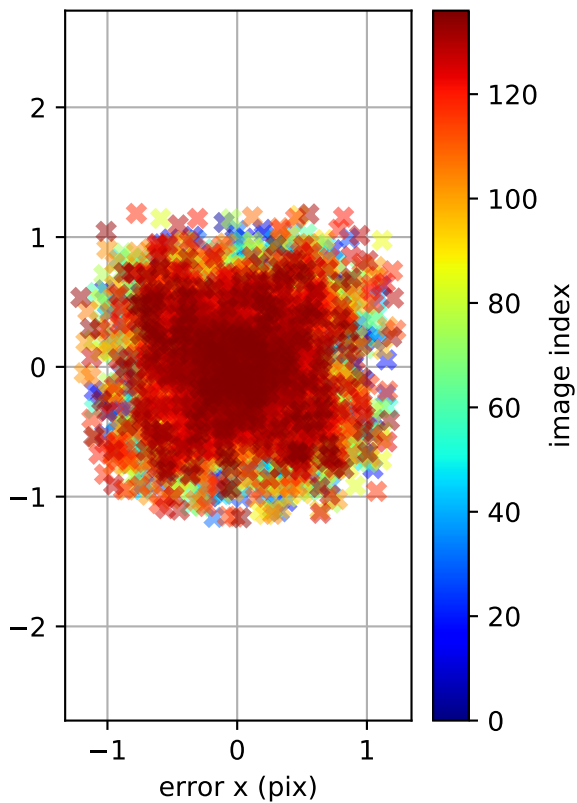
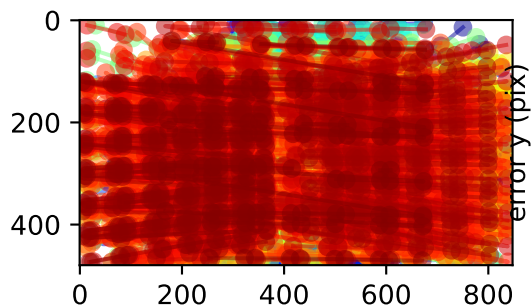
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

