

Calibration results

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Camera-system parameters:

cam0 (/ifo003/camera/infra1/image_rect_raw):

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

distortion: [0.00118725 -0.00067954 -0.00046683 0.00029842] +- [0.00080943 0.00062387 0.00021515 0.00025265]

projection: [420.38494837 422.37201899 426.48058029 235.79239332] +- [0.65810331 0.6478397 0.48664615 0.4400857]

reprojection error: [0.000002, 0.000000] +- [0.282492, 0.276941]

cam1 (/ifo003/camera/infra2/image_rect_raw):

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

distortion: [0.00129364 -0.0005862 -0.0005601 0.0001589] +- [0.00079176 0.00059787 0.00021579 0.00025384]

projection: [420.44955459 422.40254828 426.6360719 235.66210483] +- [0.65975481 0.65002487 0.48933667 0.43976473]

reprojection error: [-0.000002, -0.000000] +- [0.274223, 0.277332]

baseline T_1_0:

q: [0.00007129 -0.00032483 0.00003548 0.99999994] +- [0.00035482 0.00071823 0.00006102]

t: [-0.04994975 -0.00002161 -0.00001256] +- [0.0000694 0.0000689 0.00015654]

Target configuration

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Type: aprilgrid

Tags:

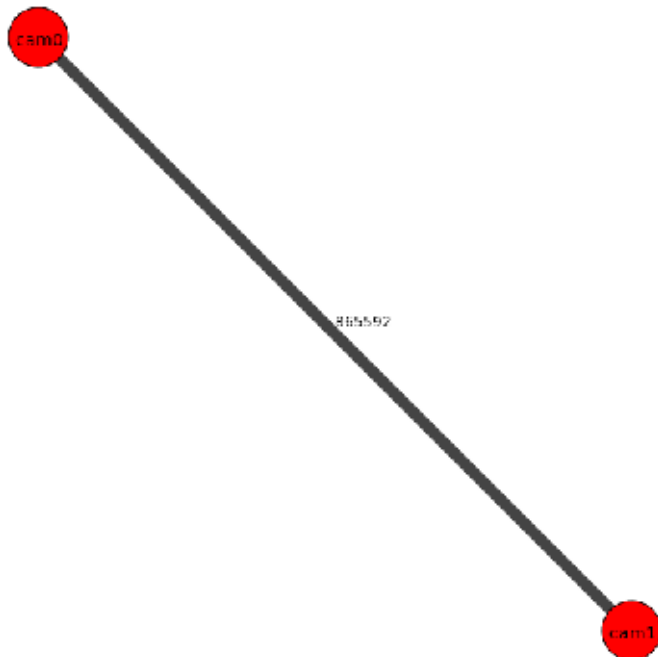
Rows: 6

Cols: 6

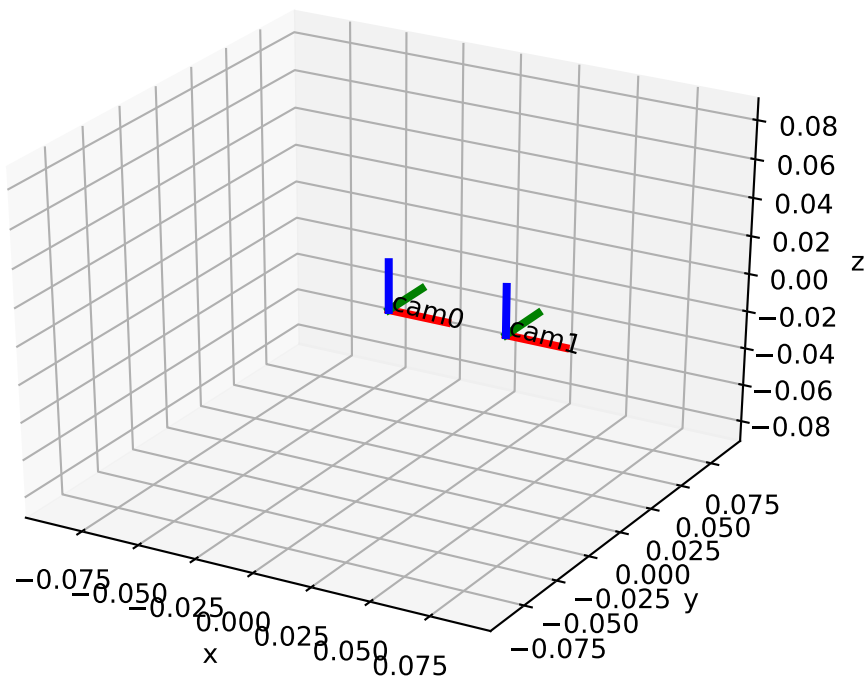
Size: 0.0625 [m]

Spacing 0.01875 [m]

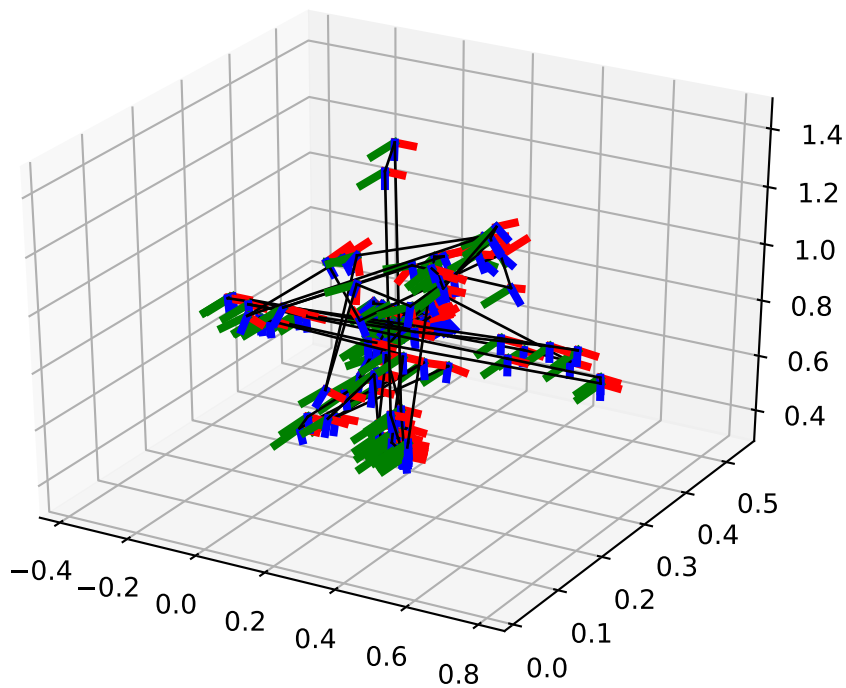
Inter-camera observations graph (edge weight=#mutual obs.)



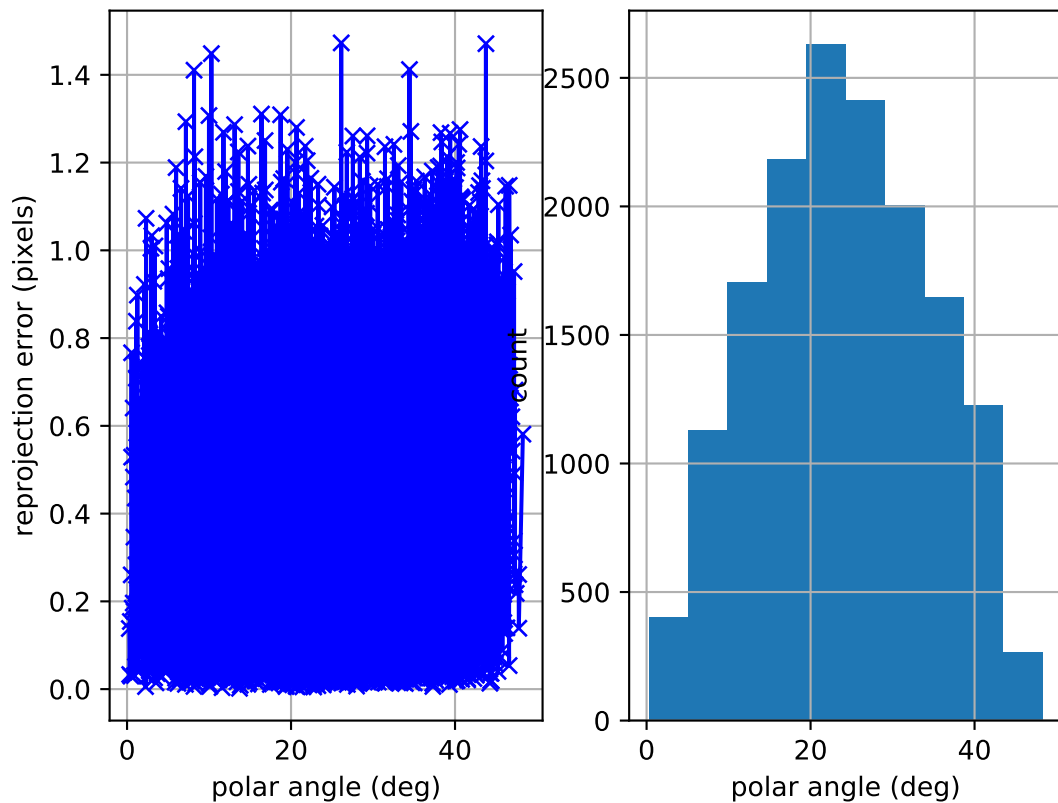
camera system



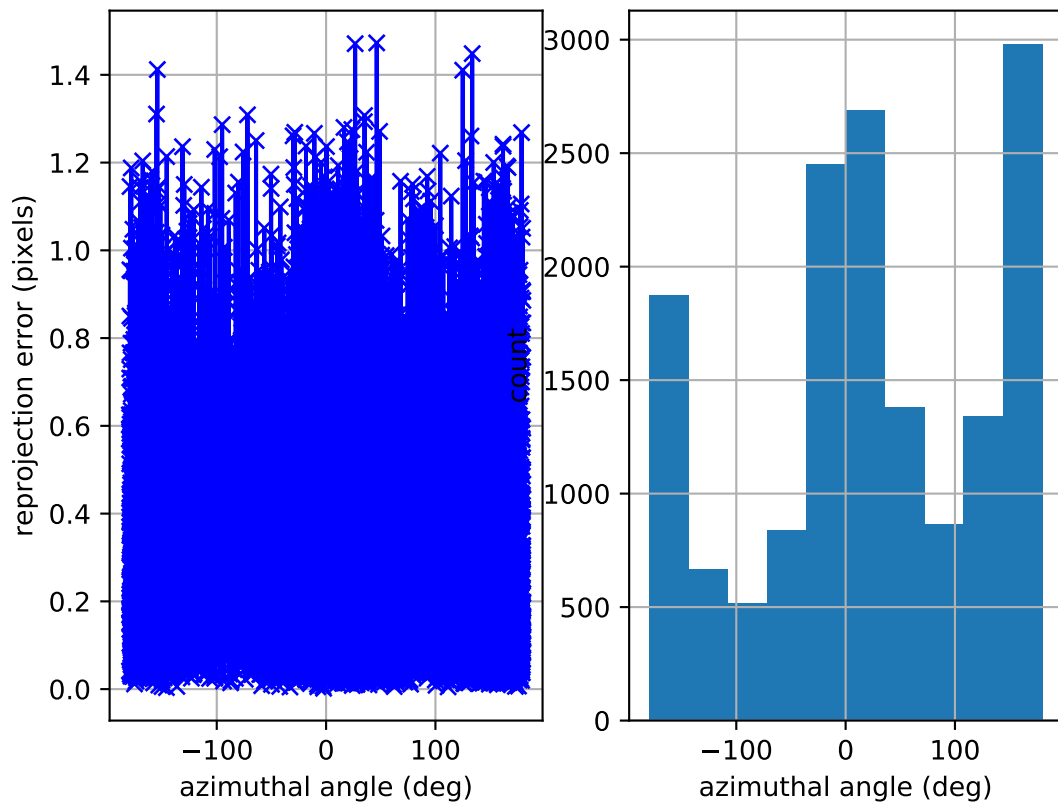
cam0: estimated poses



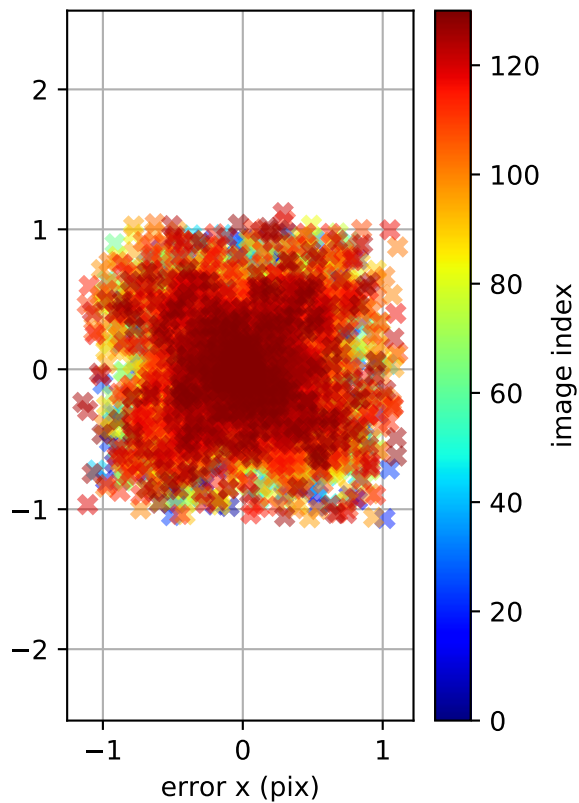
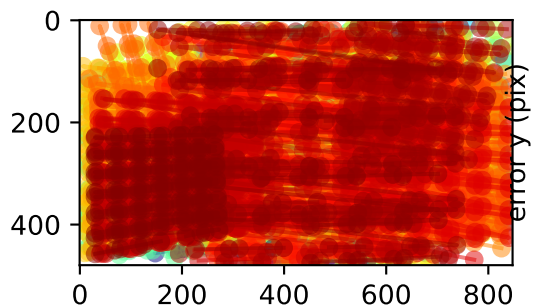
cam0: polar error



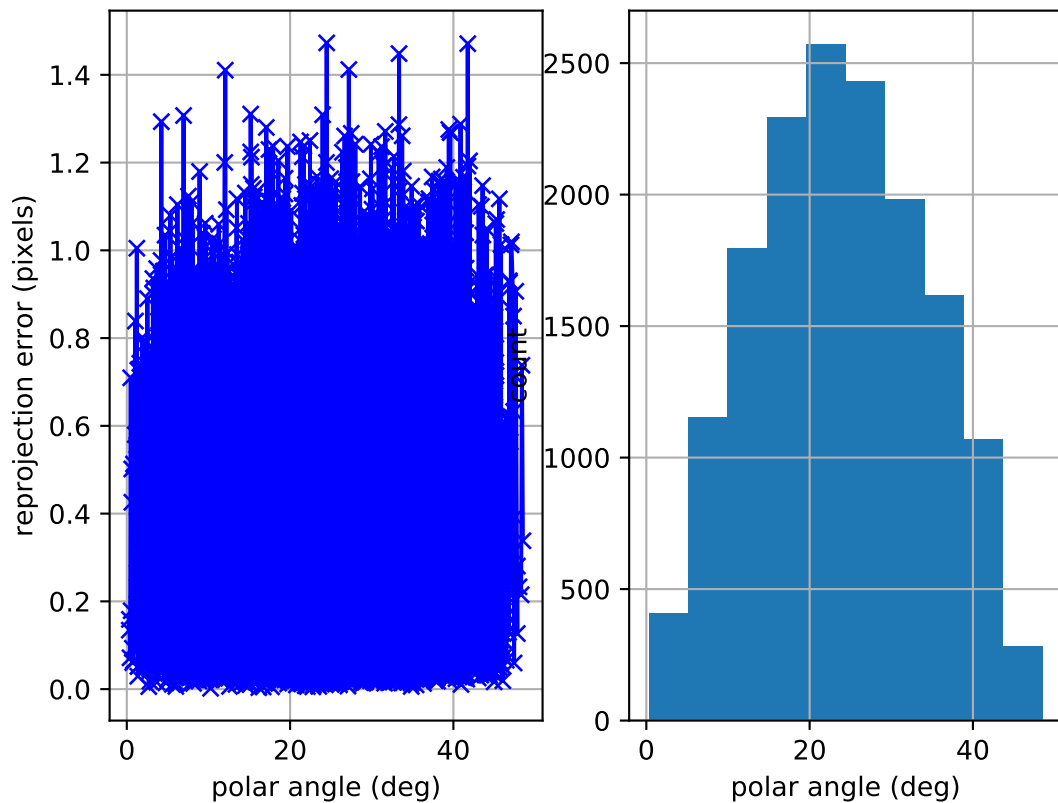
cam0: azimuthal error



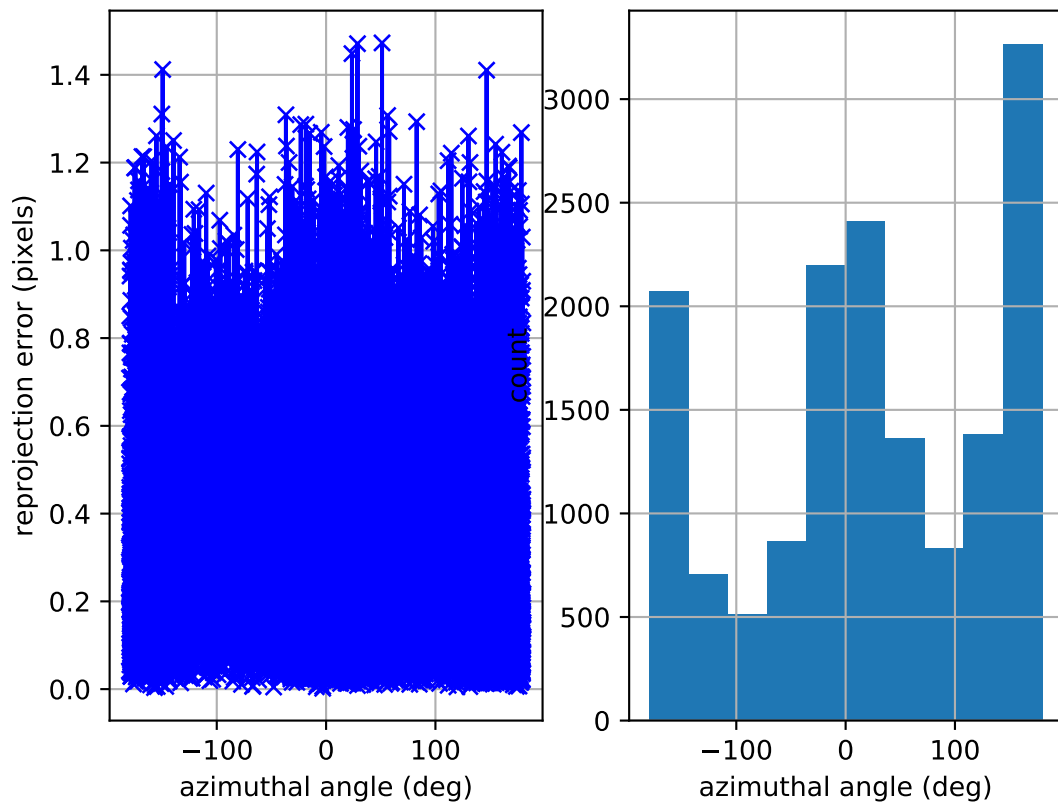
cam0: reprojection errors



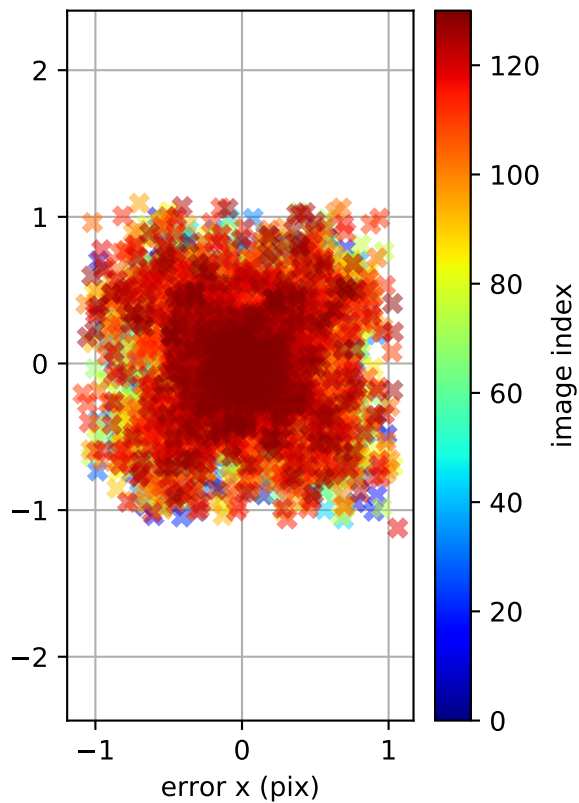
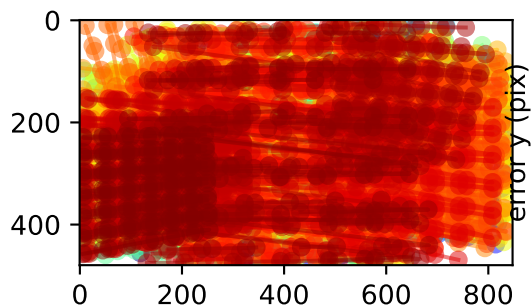
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

