

Calibration results

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Camera-system parameters:

cam0 (/infra_left):

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

distortion: [-0.01378805 0.00227879 0.00071733 -0.0063414] +- [0.00233533 0.00246617 0.00037955 0.00055197]

projection: [391.03207706 387.94564334 314.83224318 243.05566307] +- [1.11362056 1.03896628 0.71436124 0.60381196]

reprojection error: [-0.000007, 0.000000] +- [0.390063, 0.257365]

cam1 (/infra_right):

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

distortion: [-0.00432638 -0.00836068 0.00019896 -0.00651733] +- [0.00281767 0.00467738 0.00046878 0.00052933]

projection: [390.92818901 388.52174683 316.74730795 242.10328698] +- [1.05578955 1.00746434 0.69152517 0.63661452]

reprojection error: [0.000007, -0.000001] +- [0.319007, 0.260226]

baseline T_1_0:

q: [0.00102065 0.00091074 -0.00015745 0.99999905] +- [0.00143744 0.0015749 0.00017805]

t: [-0.04972812 -0.00003667 0.00142319] +- [0.00014644 0.00010936 0.00040874]

Target configuration

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Type: aprilgrid

Tags:

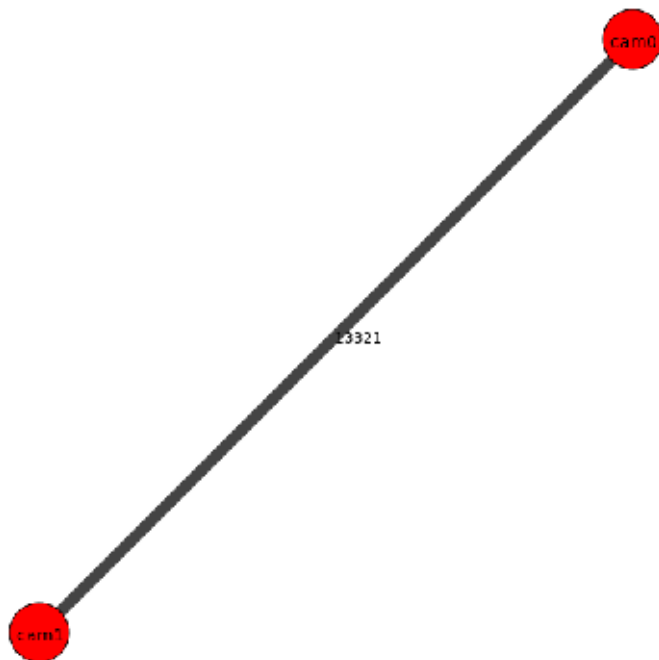
Rows: 6

Cols: 6

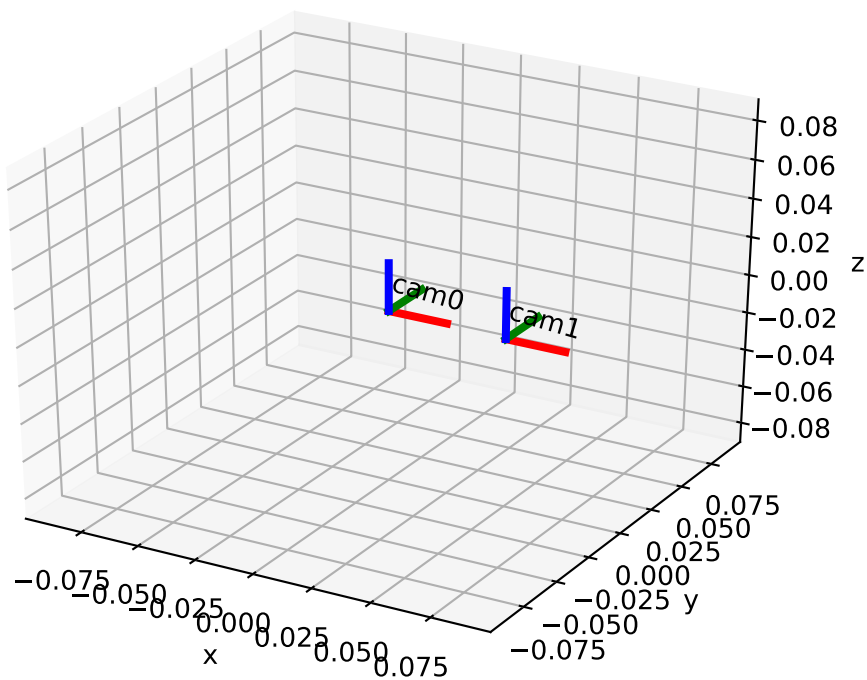
Size: 0.02 [m]

Spacing 0.006 [m]

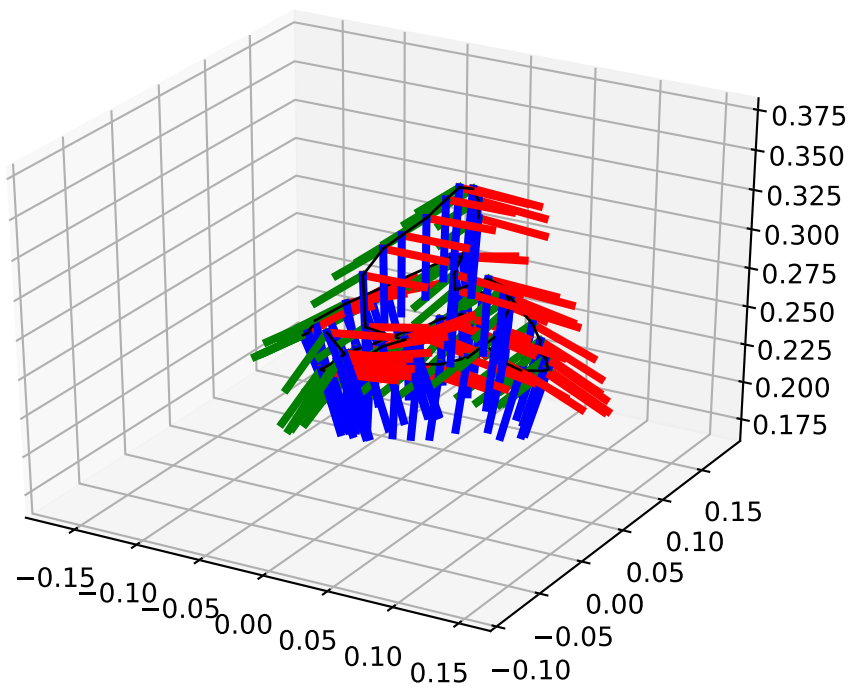
Inter-camera observations graph (edge weight=#mutual obs.)



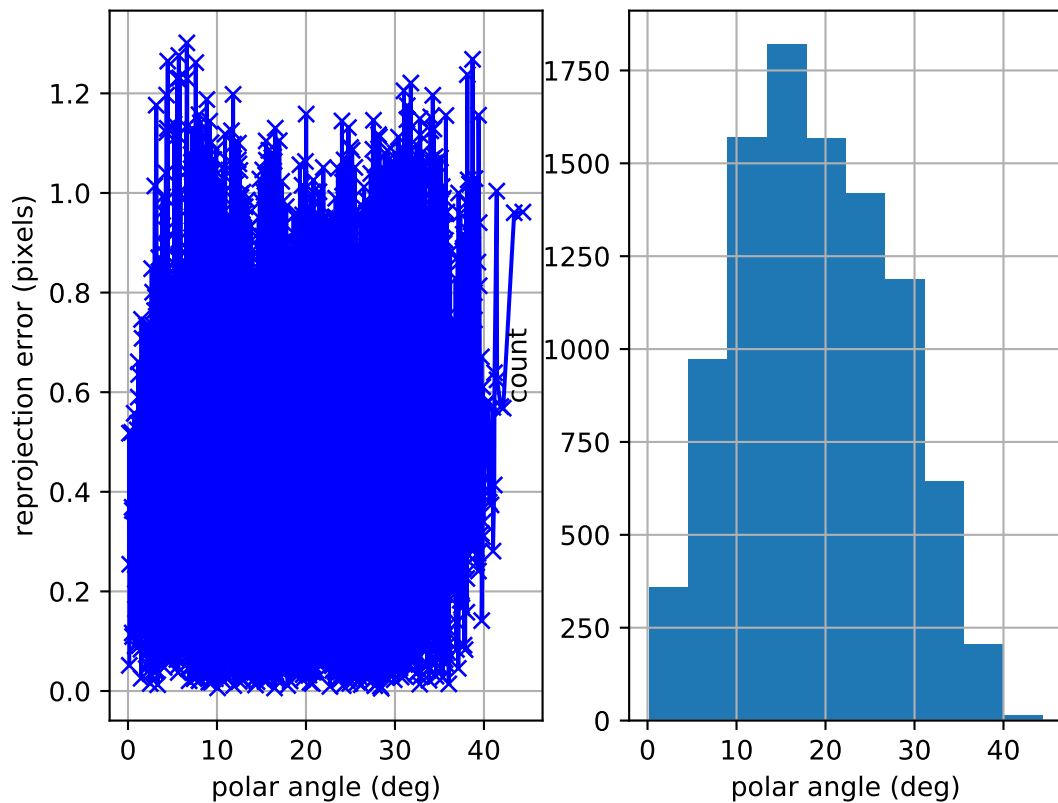
camera system



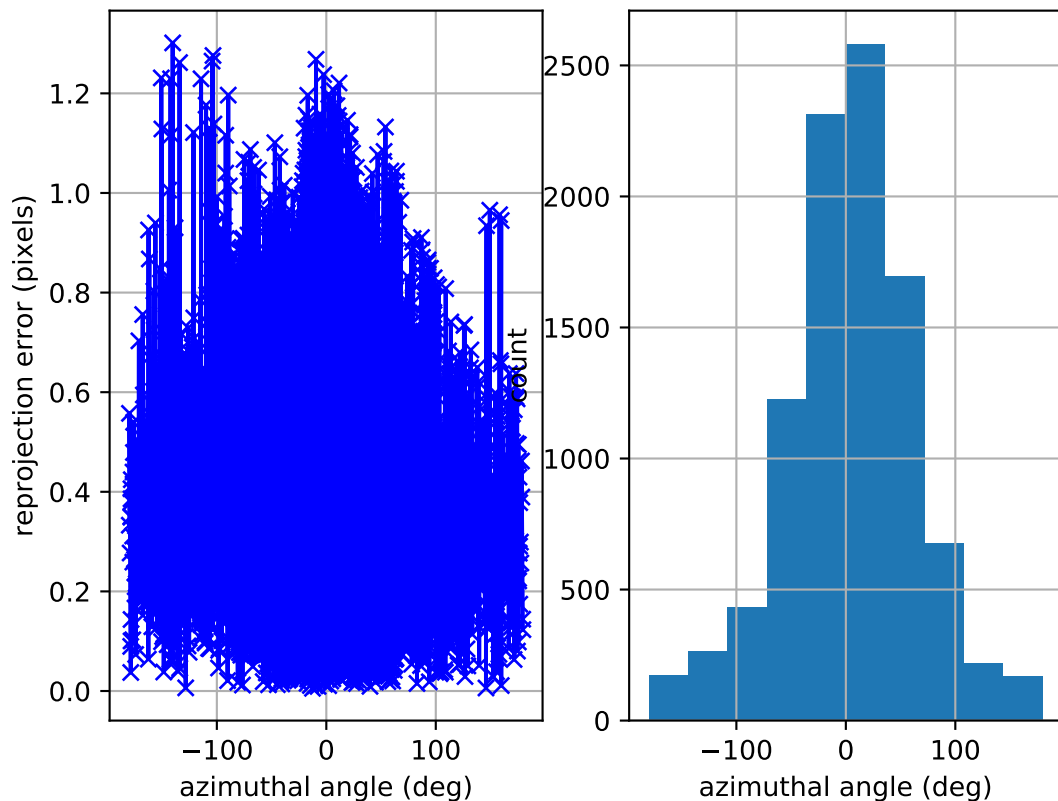
cam0: estimated poses



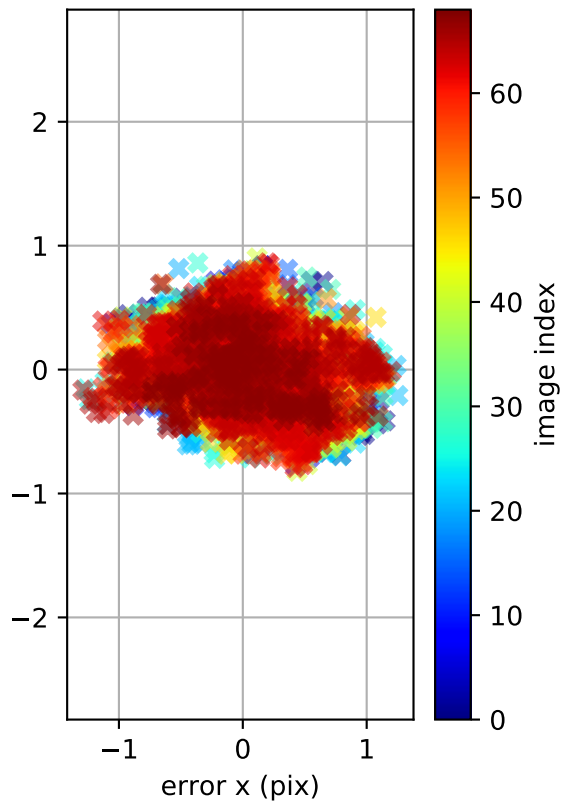
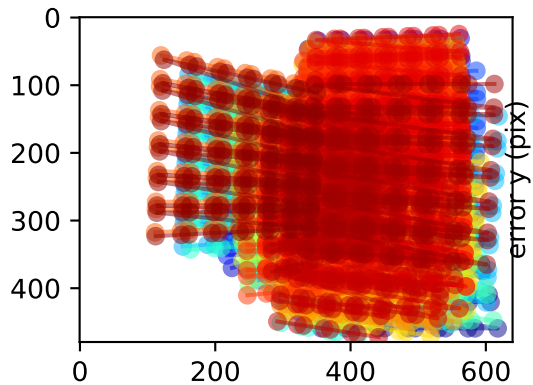
cam0: polar error



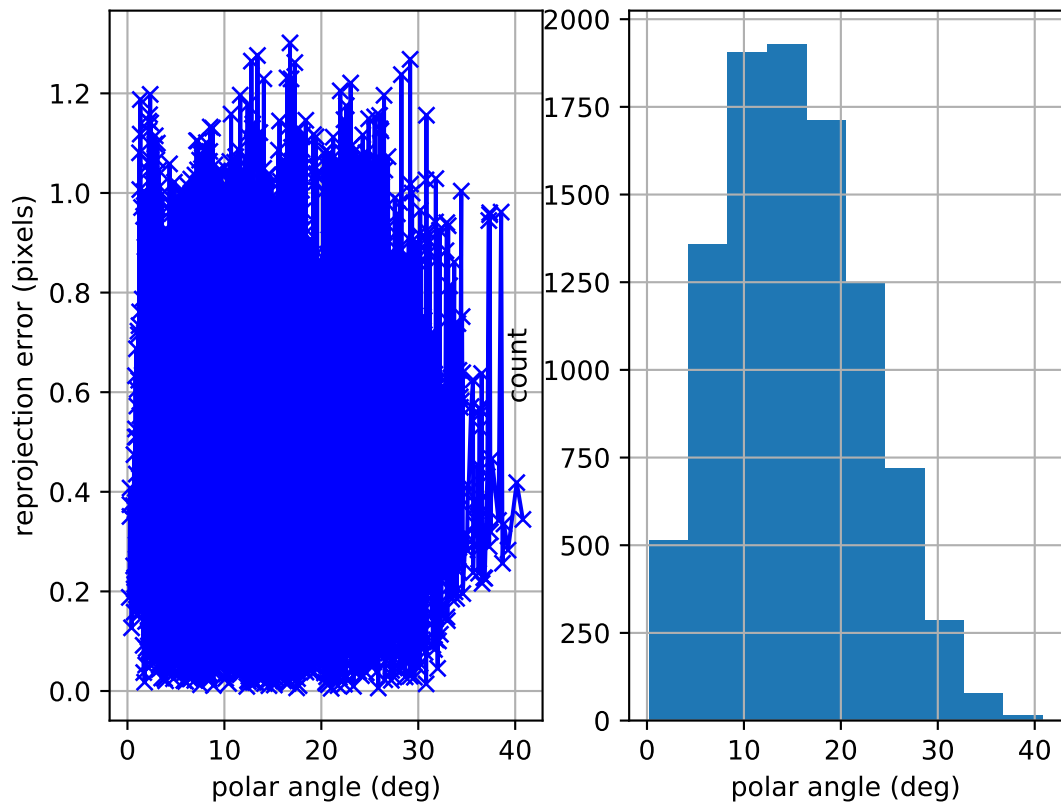
cam0: azimuthal error



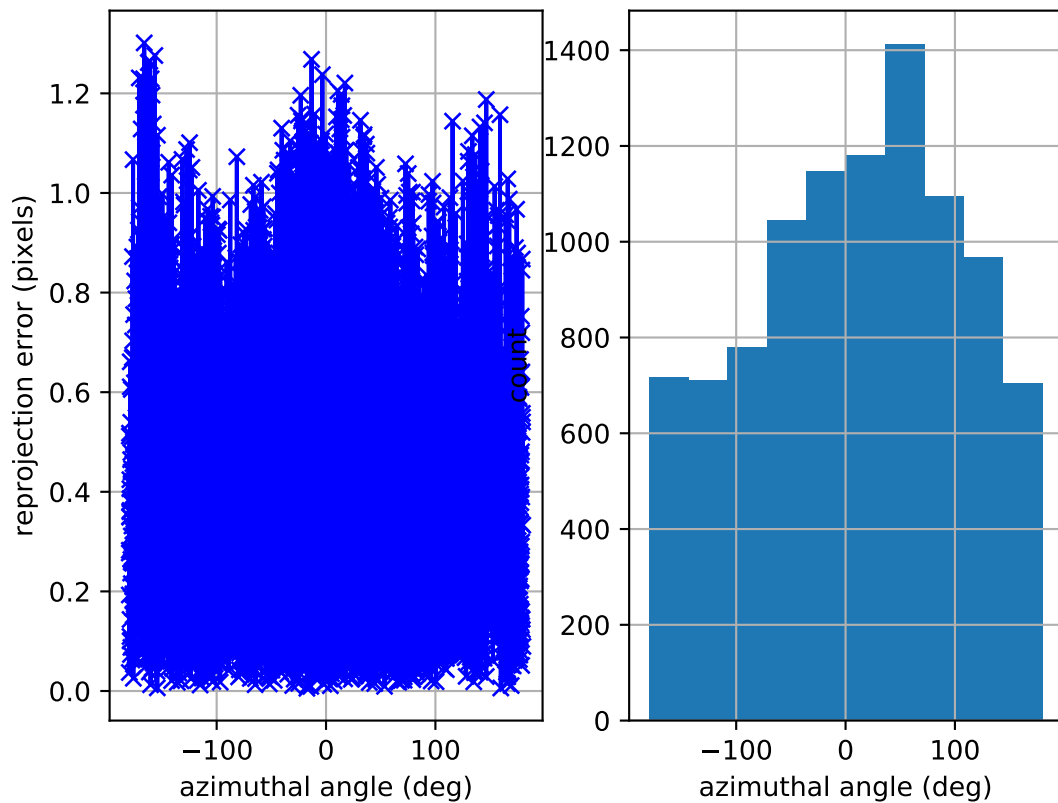
cam0: reprojection errors



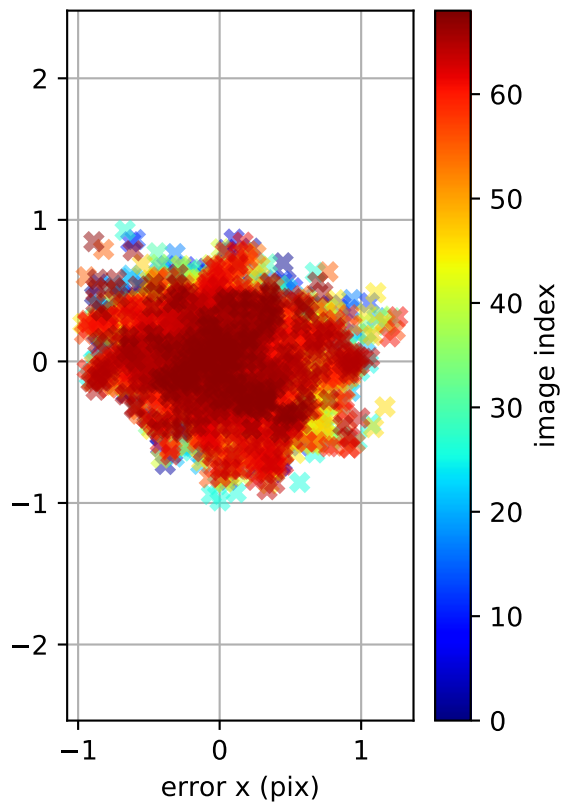
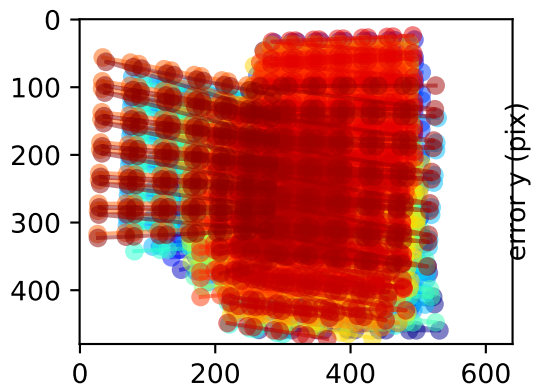
cam1: polar error



cam1: azimuthal error

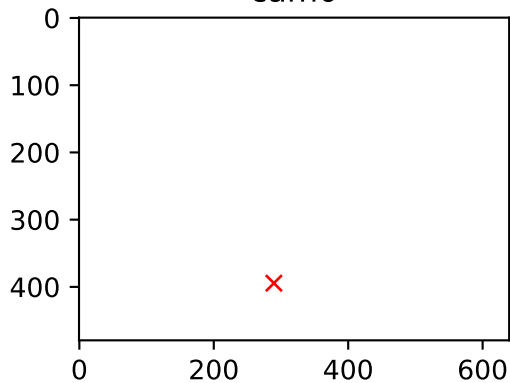


cam1: reprojection errors



Location of removed outlier corners

cam0



cam1

