

Calibration results

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Camera-system parameters:

cam0 (/camera1/camera/color/image_raw):

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

distortion: [0.0828111 -0.18398758 0.00505113 0.00864026] +- [0.00297666 0.00725833 0.00029065 0.00027329]

projection: [600.91794426 599.25783878 341.60463277 240.44821508] +- [0.26825093 0.27105073 0.27514822 0.41232325]

reprojection error: [-0.001374, 0.000555] +- [0.381953, 0.520033]

cam1 (/camera2/camera/color/image_raw):

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

distortion: [0.07602073 -0.16036282 0.00719125 -0.00142781] +- [0.00676401 0.02445469 0.0004008 0.00034712]

projection: [588.50583776 586.45726964 333.63851869 247.93536548] +- [0.13419476 0.12310157 0.00482458 0.01553035]

reprojection error: [-0.000265, 0.000015] +- [0.407544, 0.477097]

cam2 (/camera3/camera/color/image_raw):

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

distortion: [0.09318341 -0.23029164 0.00015458 -0.00087505] +- [0.00432493 0.01034575 0.00025936 0.00040073]

projection: [607.43670399 607.15371224 318.51127113 242.77602441] +- [0.40796813 0.39705313 0.01859791 0.28903132]

reprojection error: [-0.000124, -0.000377] +- [0.384998, 0.411345]

baseline T_1_0:

q: [-0.0625497 0.90123013 0.24184897 0.35409161] +- [0.00080208 0.001094 0.00057247]

t: [0.88834744 -0.82096896 2.98472933] +- [0.00136318 0.00087265 0.00088646]

baseline T_2_1:

q: [0.00057219 -0.75677309 -0.30172542 0.5798758] +- [0.00072163 0.0006907 0.00031699]

t: [-1.50462459 -0.78795595 2.16028215] +- [0.00063563 0.00117637 0.00188136]

Target configuration

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Type: aprilgrid

Tags:

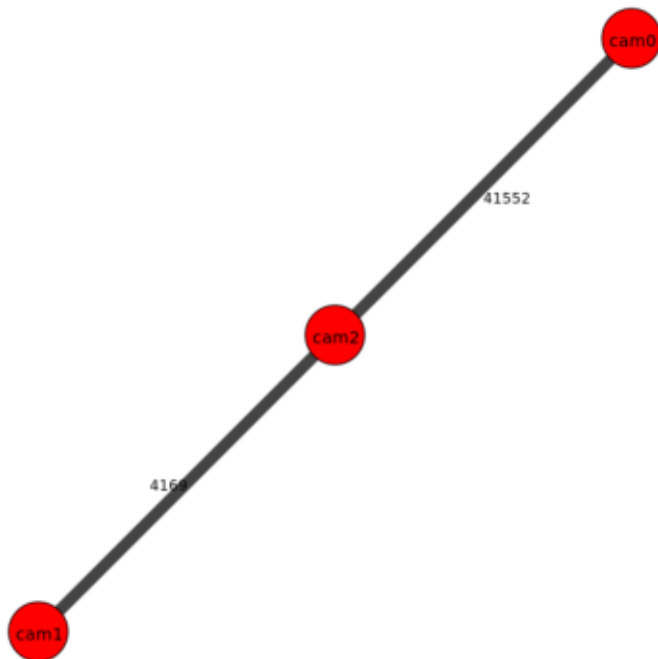
Rows: 6

Cols: 8

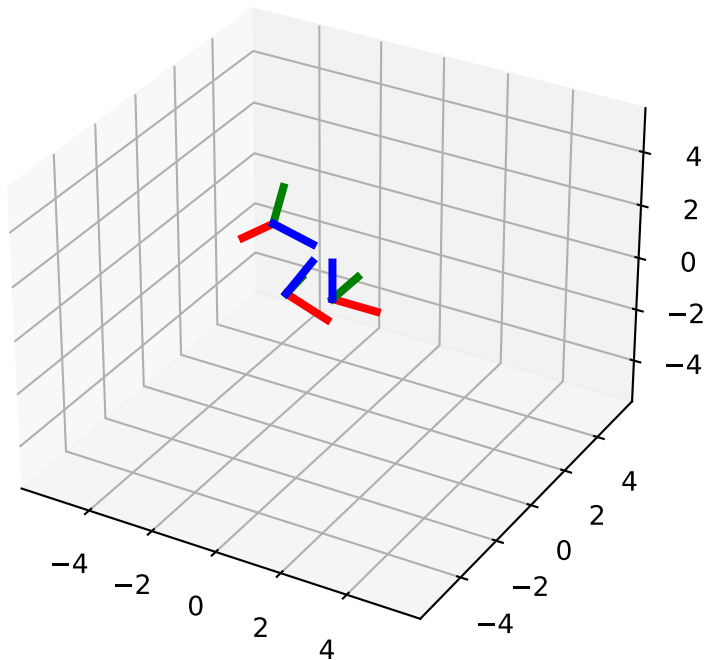
Size: 0.078 [m]

Spacing 0.007800000000000005 [m]

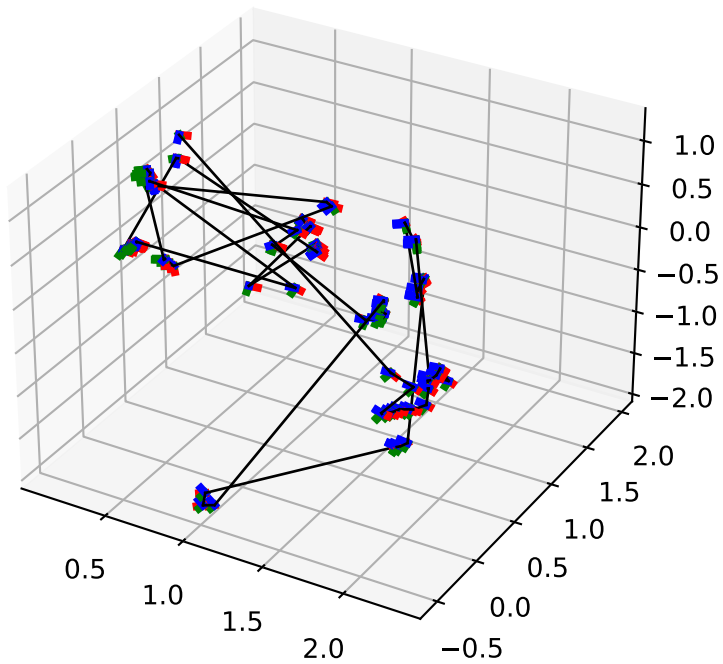
Inter-camera observations graph (edge weight=#mutual obs.)



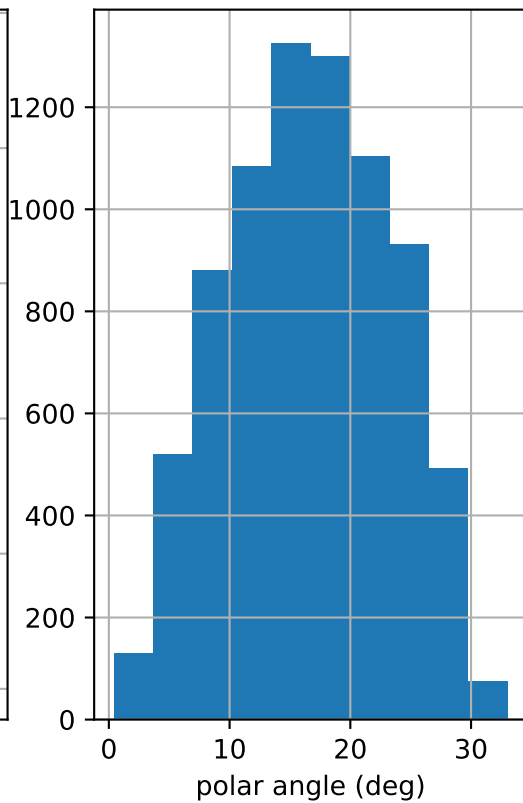
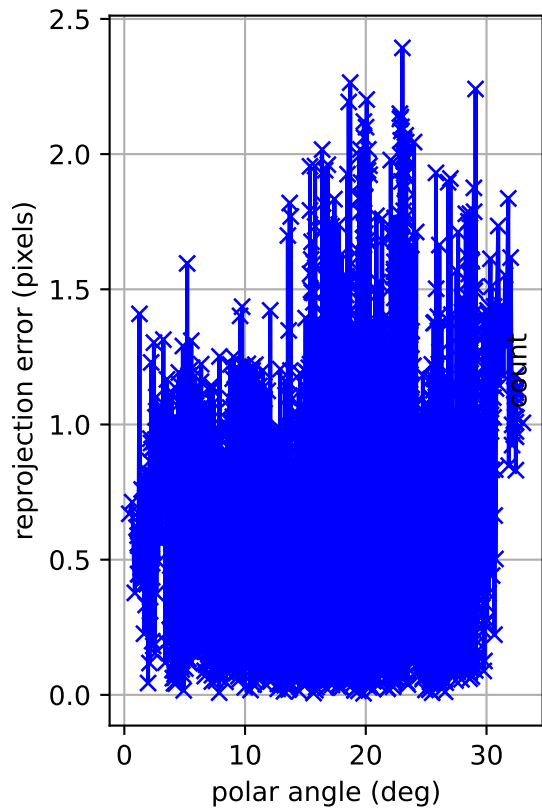
camera system



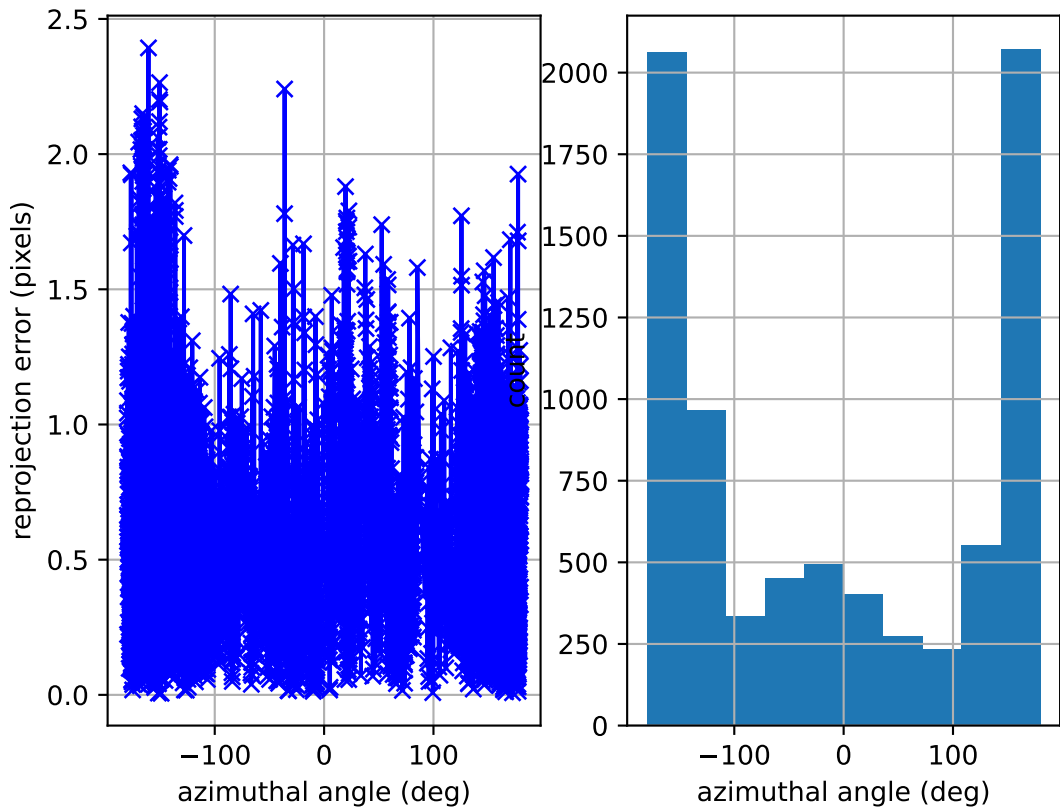
cam0: estimated poses



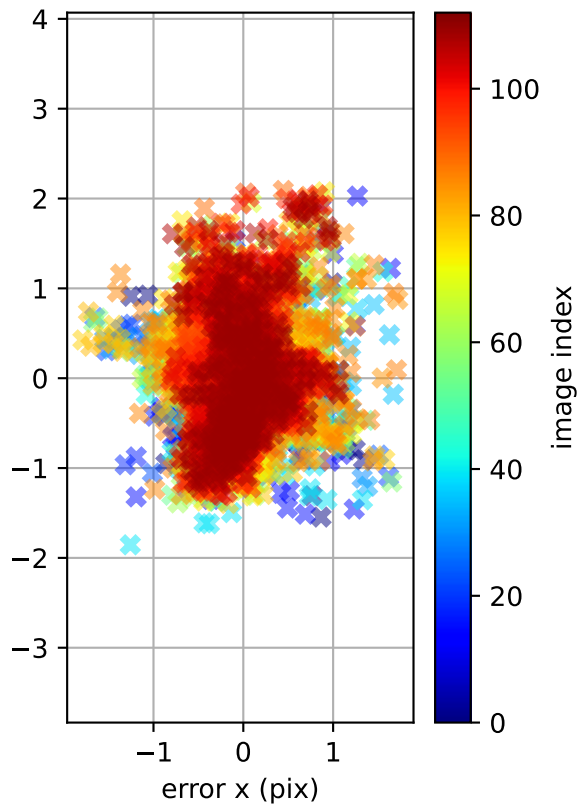
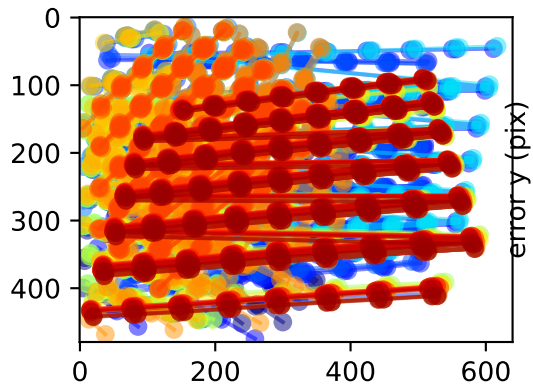
cam0: polar error



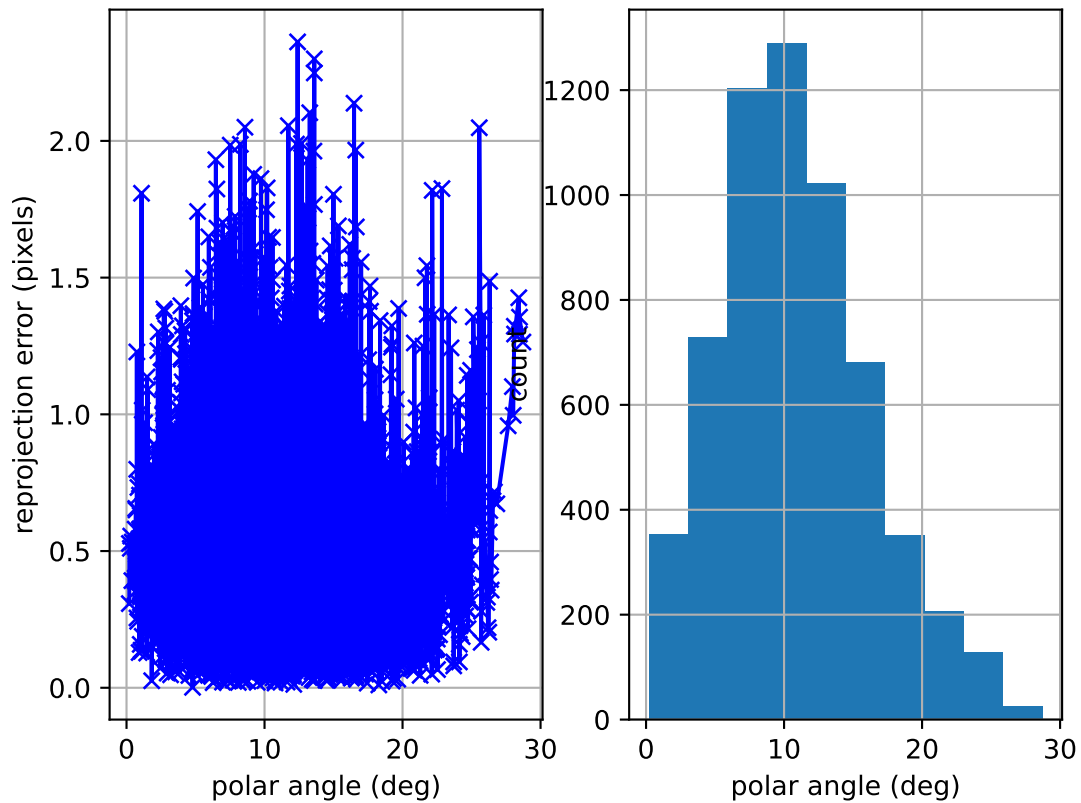
cam0: azimuthal error



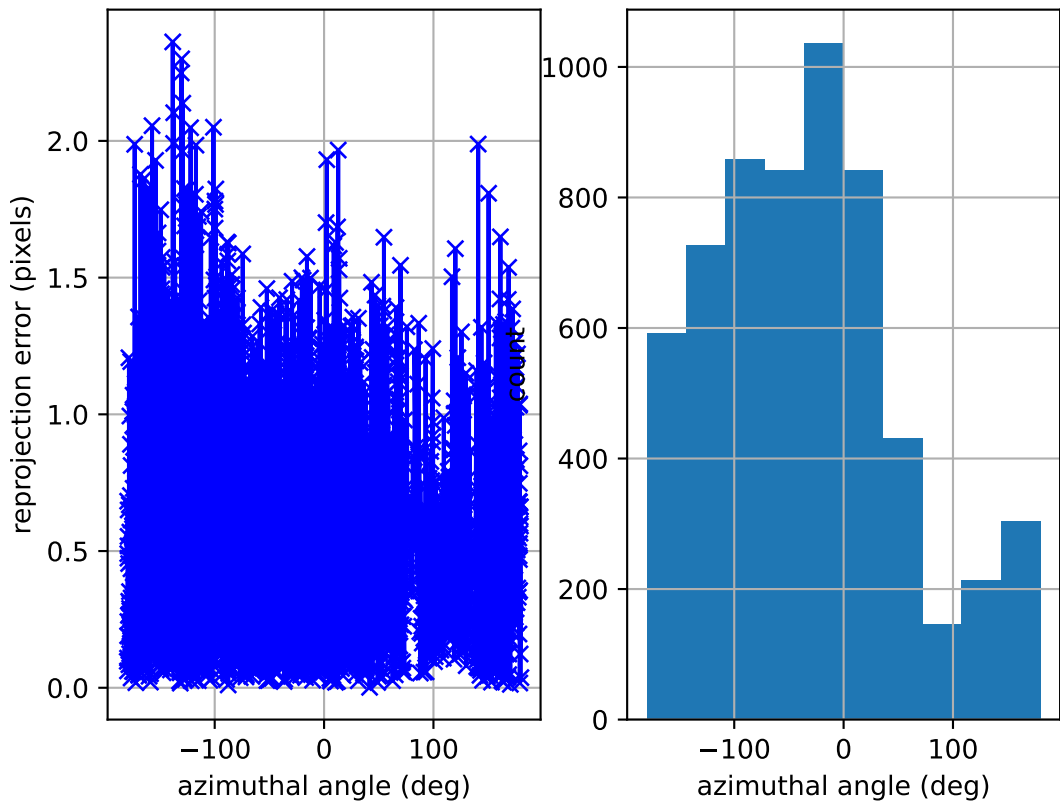
cam0: reprojection errors



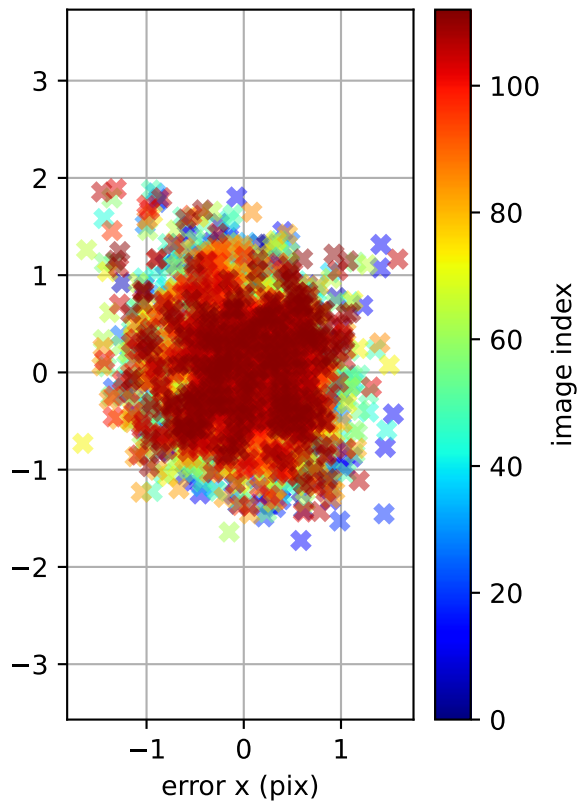
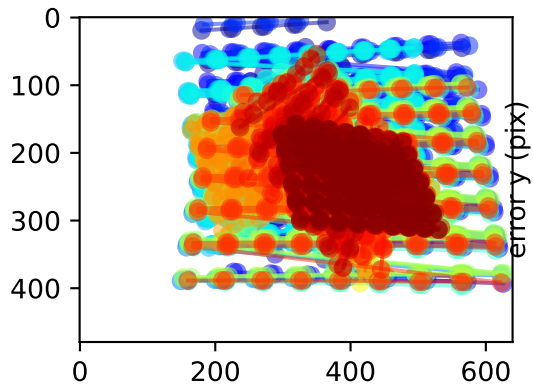
cam1: polar error



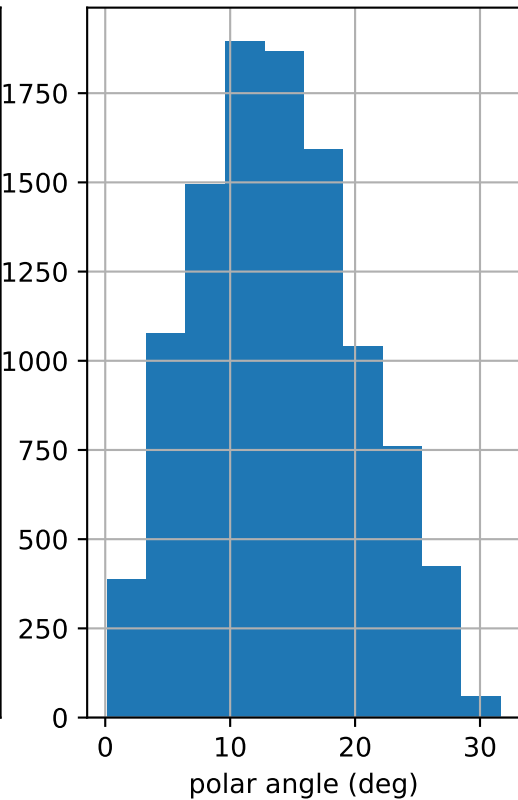
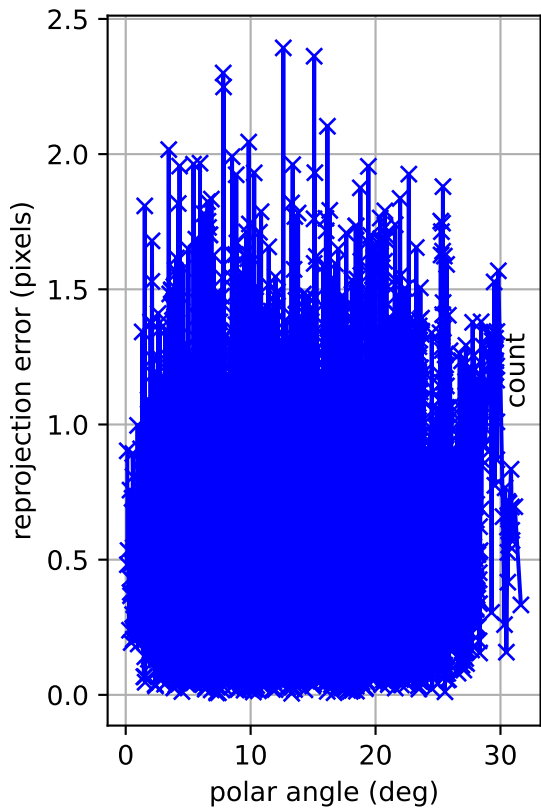
cam1: azimuthal error



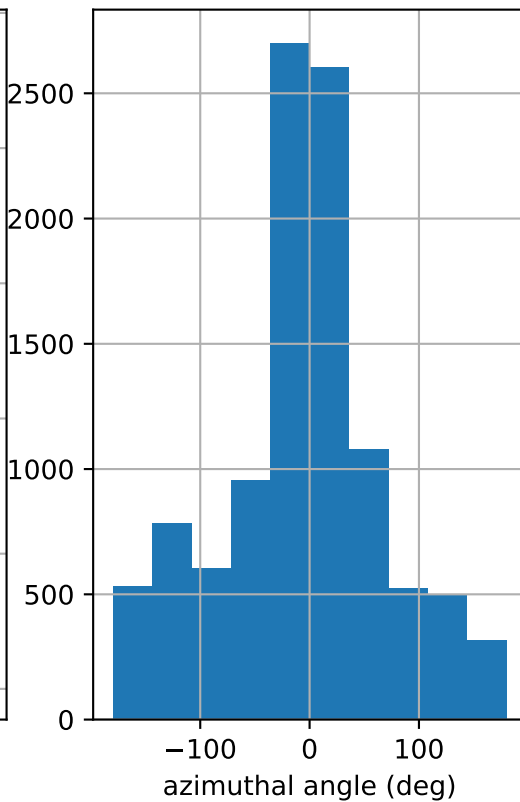
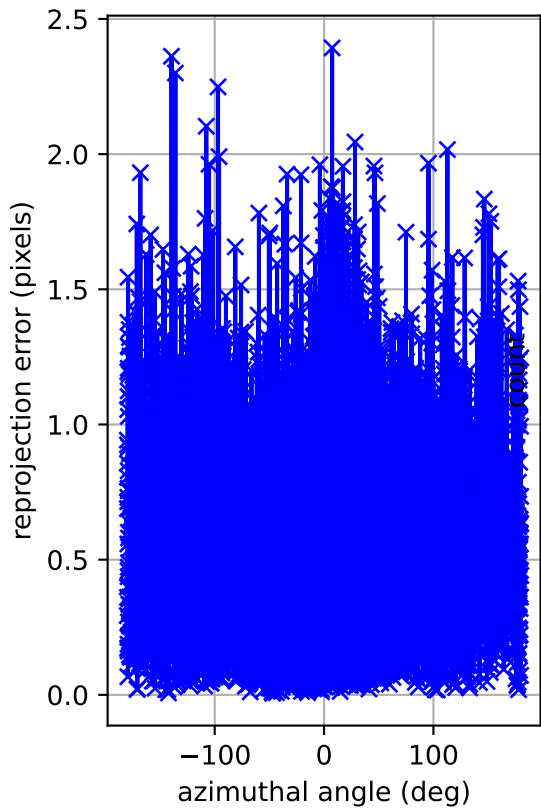
cam1: reprojection errors



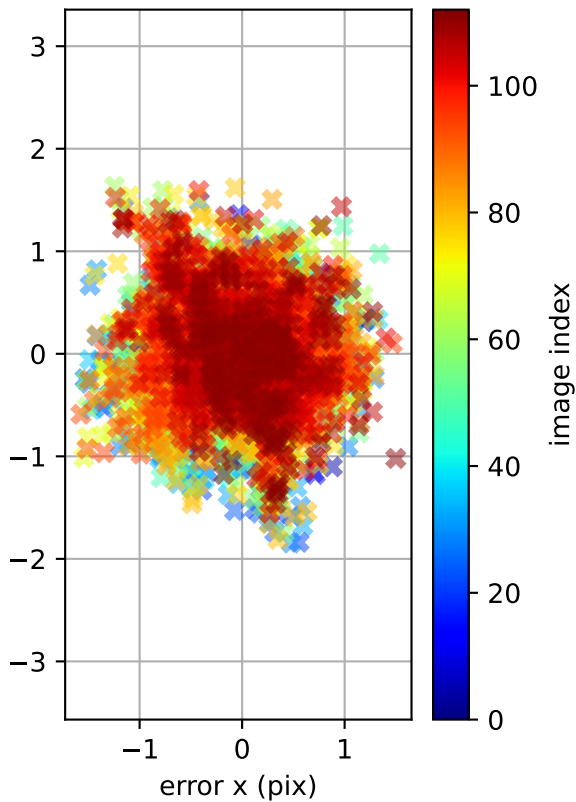
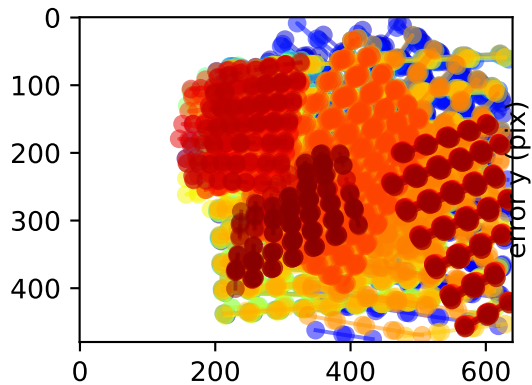
cam2: polar error



cam2: azimuthal error

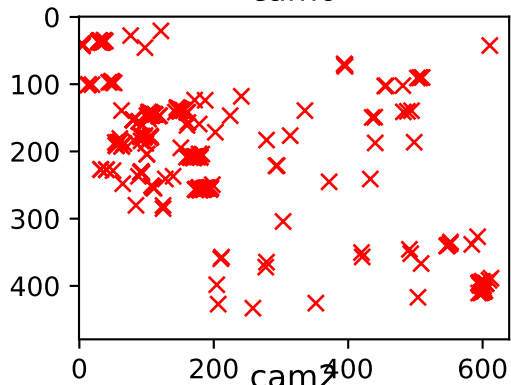


cam2: reprojection errors

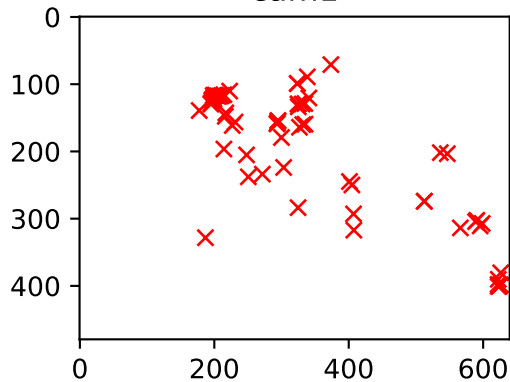


Location of removed outlier corners

cam0



cam1



cam2

