

Calibration results

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Camera-system parameters:

cam0 (/hololens_ag0/rm_vlc_leftfront/image_raw):

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

distortion: [-0.01014541 0.01025957 0.00342309 0.00364146] +- [0.00205158 0.00168084 0.00057317 0.00050761]

projection: [361.47690547 361.51369066 243.52702078 315.92877346] +- [0.18905832 0.20819502 0.86647895 0.83696142]

reprojection error: [0.000034, 0.000123] +- [0.130094, 0.128018]

cam1 (/hololens_ag0/rm_vlc_rightfront/image_raw):

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

distortion: [-0.00706162 0.00793796 0.00399075 -0.00184667] +- [0.00202848 0.00147778 0.00060006 0.00051789]

projection: [361.72812325 361.69448547 241.42893007 314.80771579] +- [0.19396284 0.22039683 0.87227408 0.86754768]

reprojection error: [0.000013, 0.000125] +- [0.125024, 0.123640]

baseline T_1_0:

q: [-0.00649401 0.01203406 0.00305933 0.99990182] +- [0.00161292 0.00125864 0.00020773]

t: [-0.0990349 -0.00001608 -0.00105905] +- [0.00010209 0.00010188 0.00027155]

Target configuration

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Type: aprilgrid

Tags:

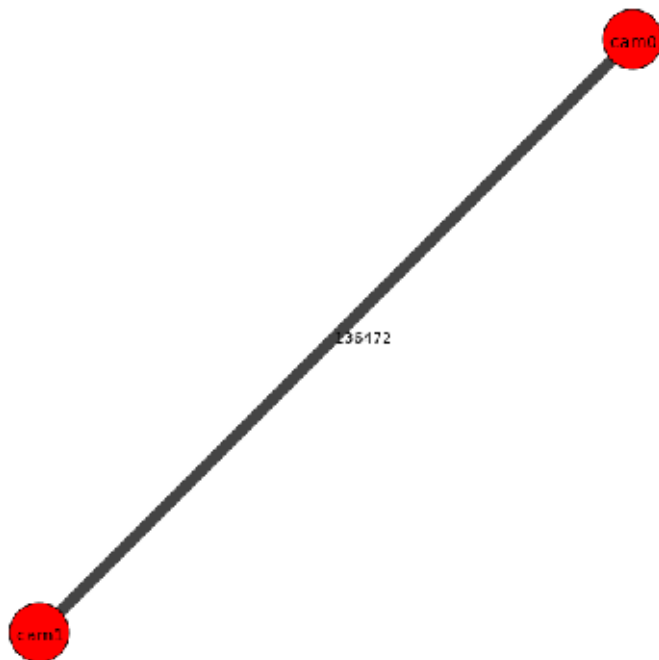
Rows: 3

Cols: 4

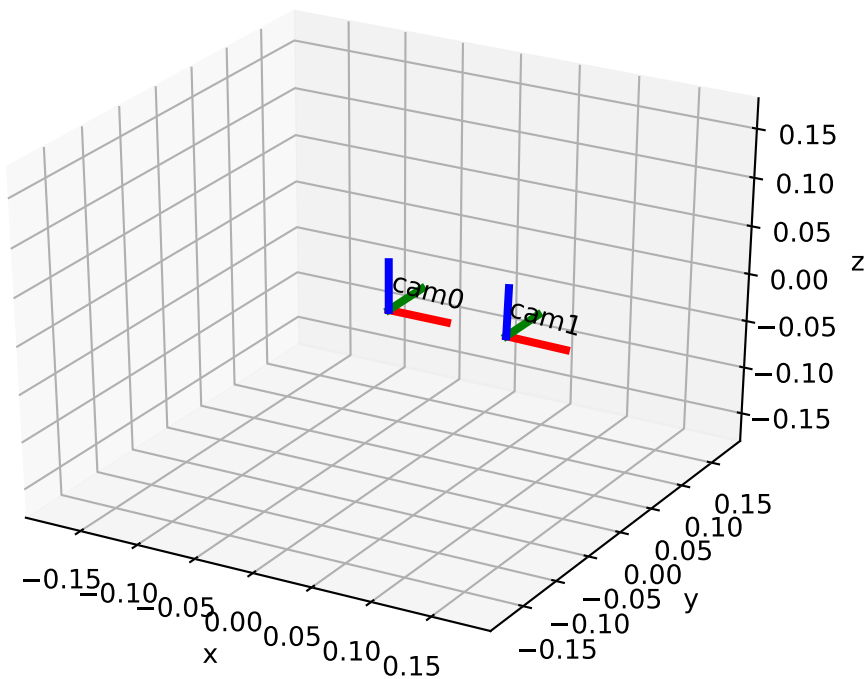
Size: 0.05 [m]

Spacing 0.0125 [m]

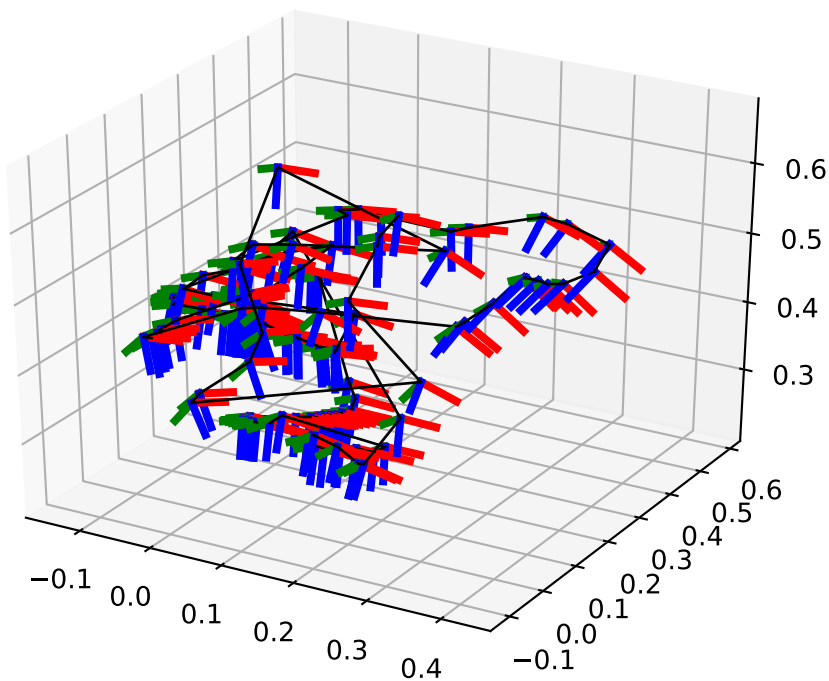
Inter-camera observations graph (edge weight=#mutual obs.)



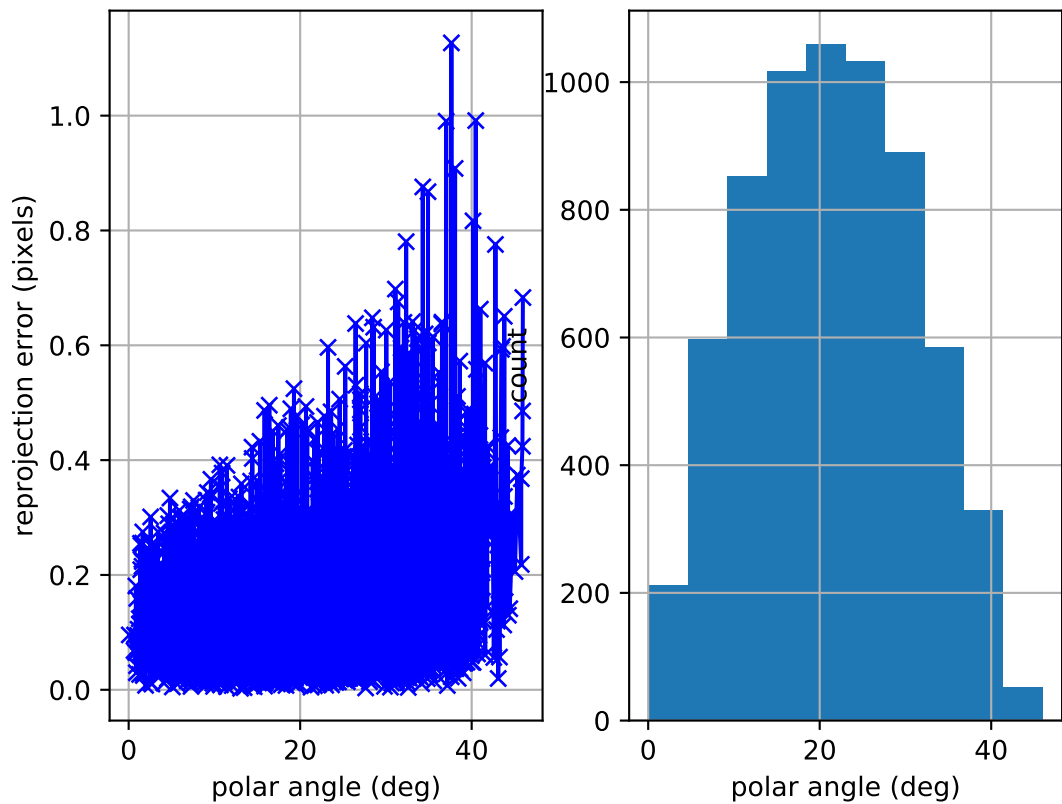
camera system



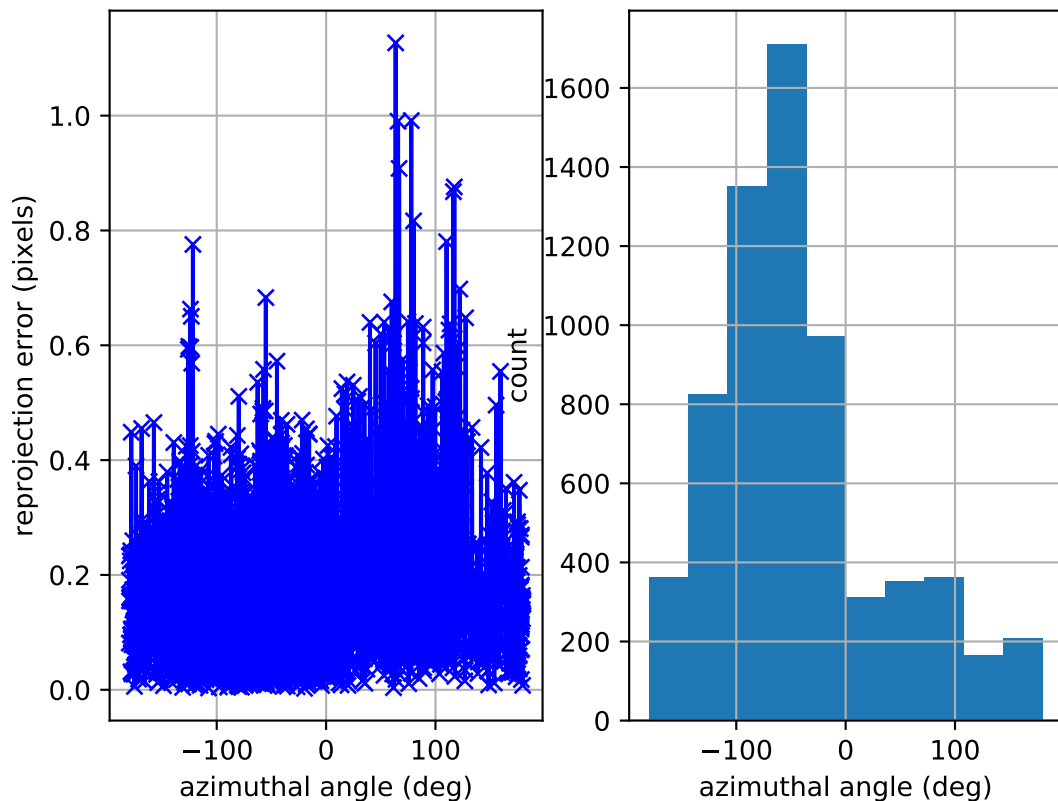
cam0: estimated poses



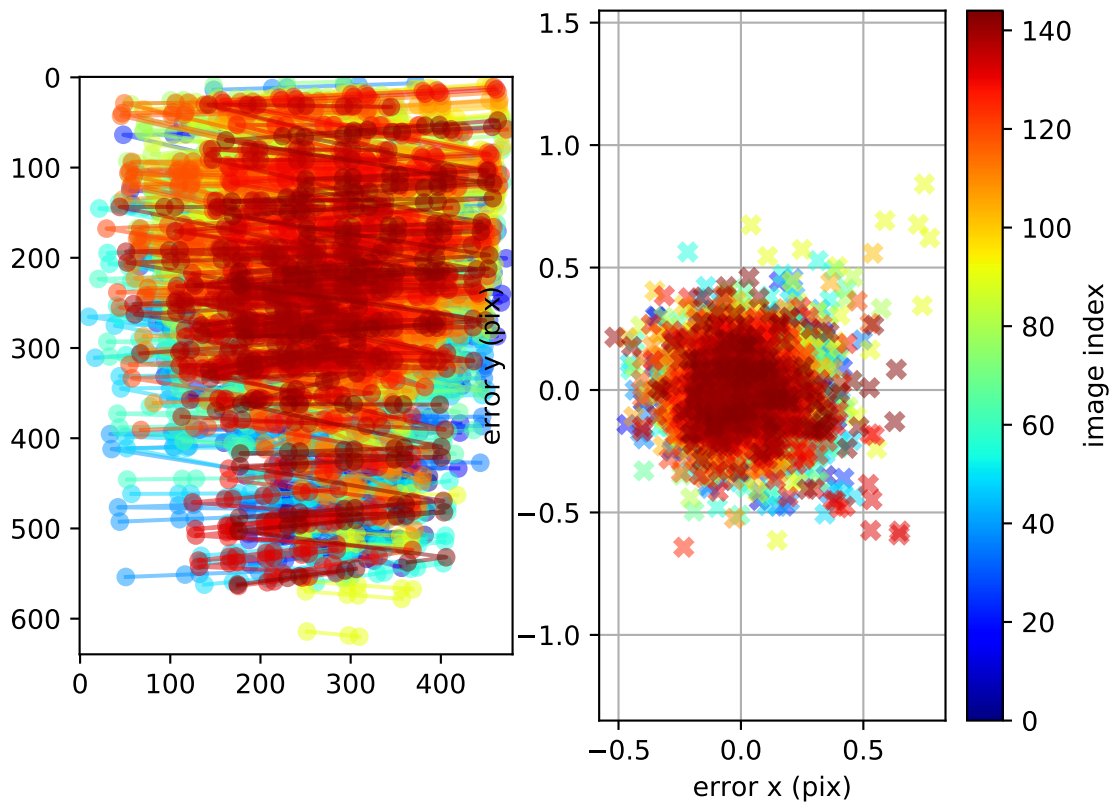
cam0: polar error



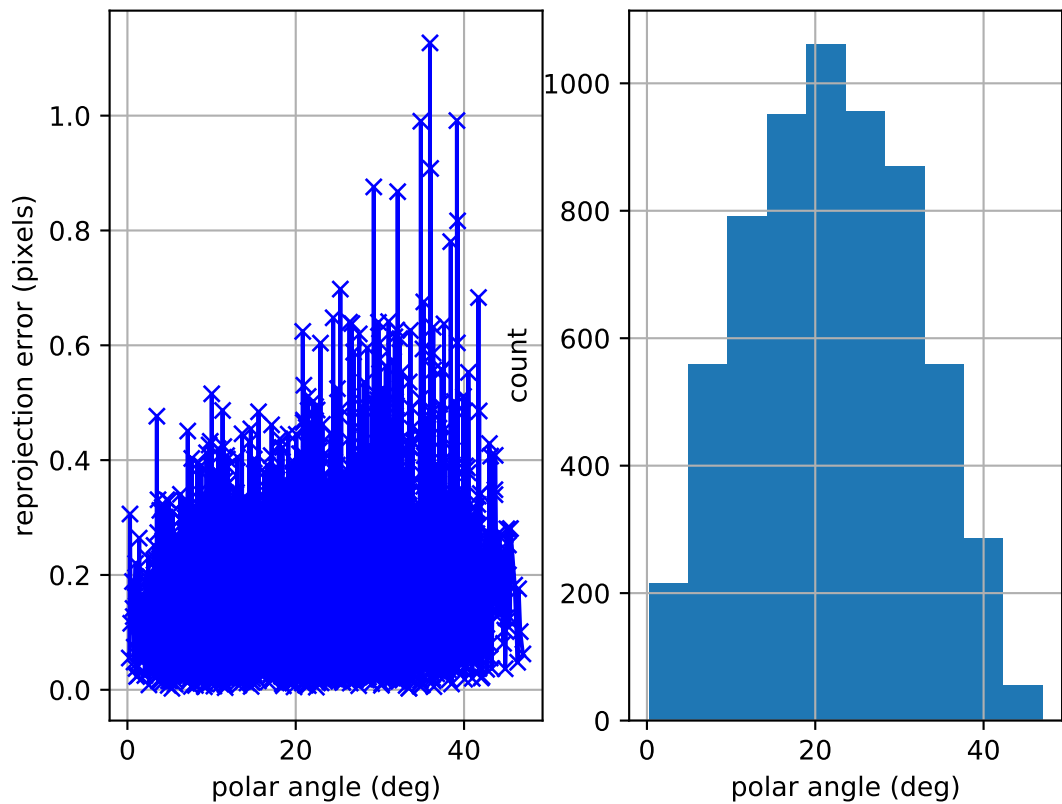
cam0: azimuthal error



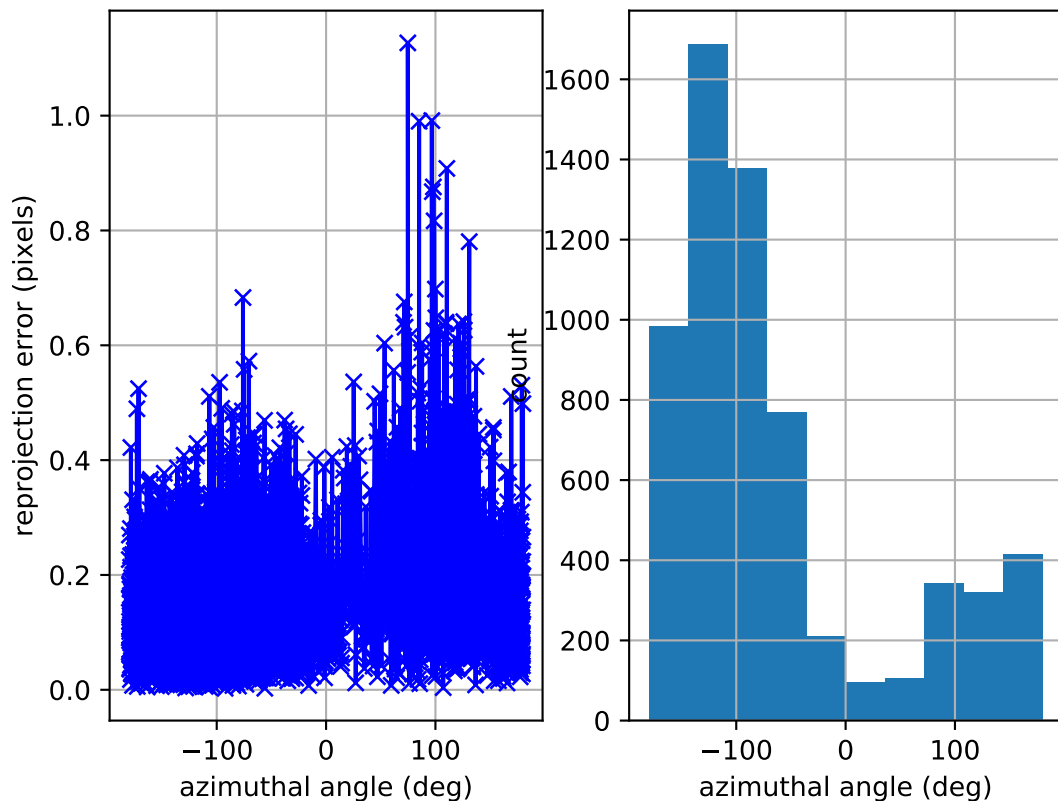
cam0: reprojection errors



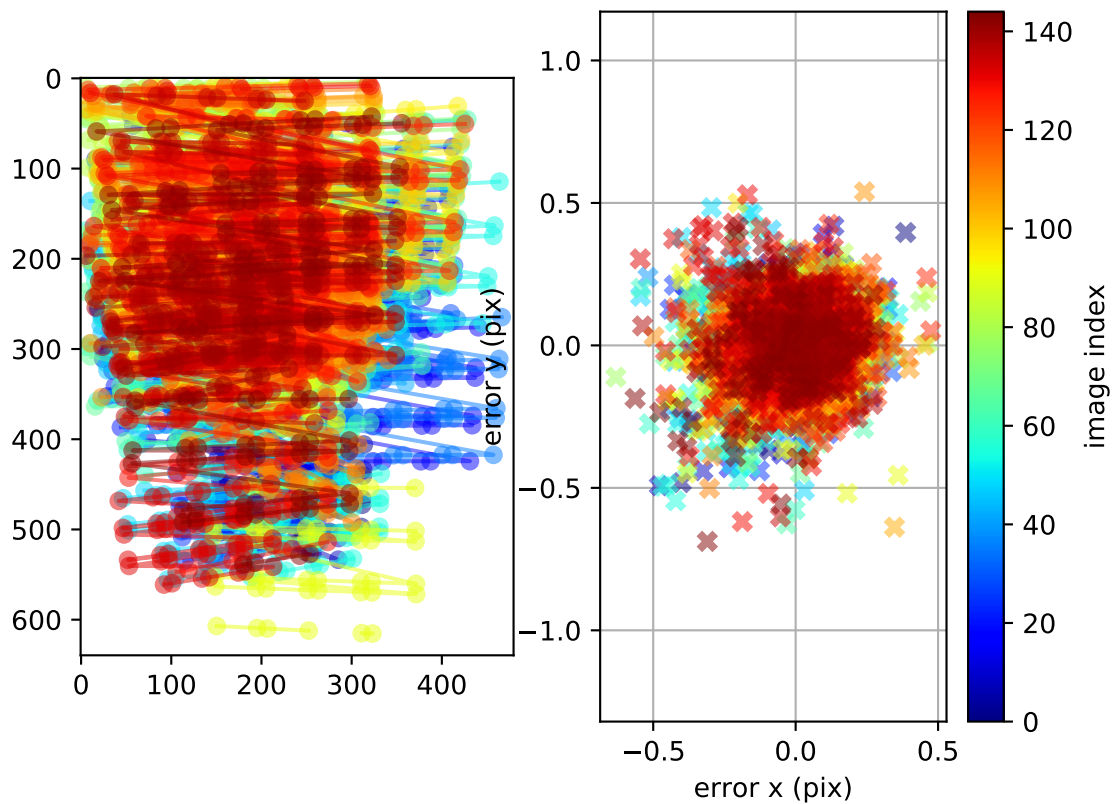
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

