

Calibration results

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Camera-system parameters:

cam0 (/camera/color/image_raw):

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

distortion: [0.14669701 -0.27353153 0.00730068 -0.003734] +- [0.00634005 0.01659217 0.00051581 0.00049105]

projection: [620.07009609 618.21021856 325.29844704 258.48711396] +- [0.3237677 0.32077982 0.10194297 0.36677119]

reprojection error: [0.000044, -0.000030] +- [0.210532, 0.154753]

cam1 (/camera/color_right/image_raw):

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

distortion: [0.14148691 -0.26292268 0.00708119 -0.00551033] +- [0.00640688 0.01709707 0.00052094 0.00048844]

projection: [620.72054306 618.54834147 322.2771521 258.39052547] +- [0.32277257 0.3209669 0.10678766 0.36599395]

reprojection error: [-0.000116, -0.000034] +- [0.301911, 0.158122]

baseline T_1_0:

q: [0.00011877 -0.00248268 -0.00007587 0.99999691] +- [0.00108058 0.00042376 0.00008663]

t: [-0.00894995 -0.00004777 0.00018635] +- [0.00020148 0.00020662 0.0006064]

Target configuration

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Type: aprilgrid

Tags:

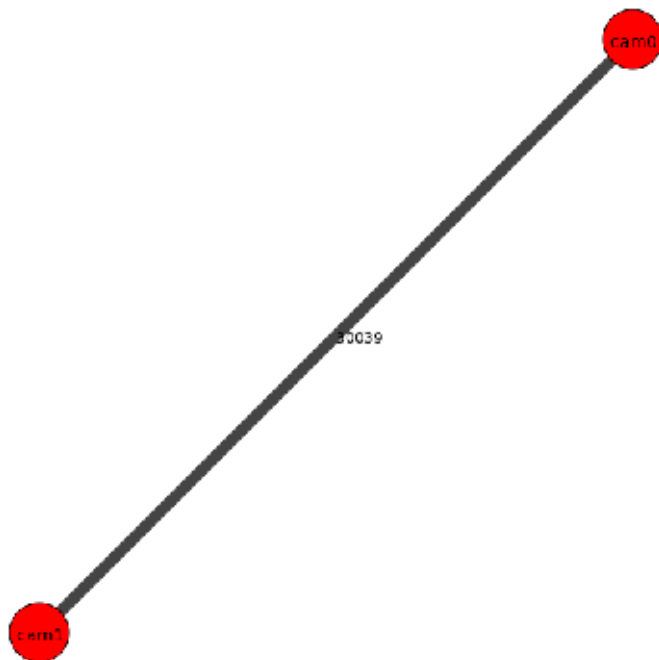
Rows: 6

Cols: 6

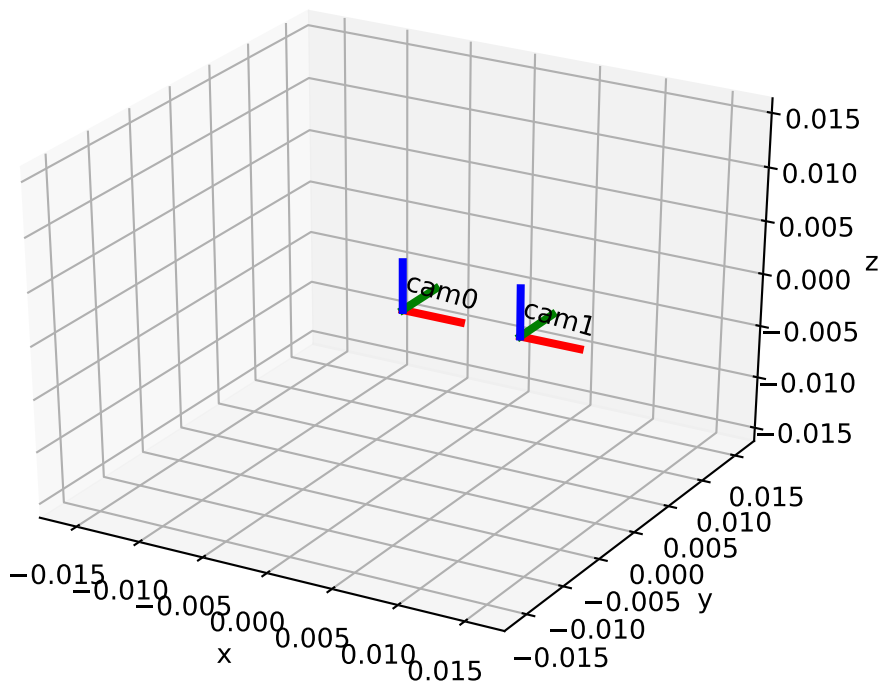
Size: 0.021 [m]

Spacing 0.00651 [m]

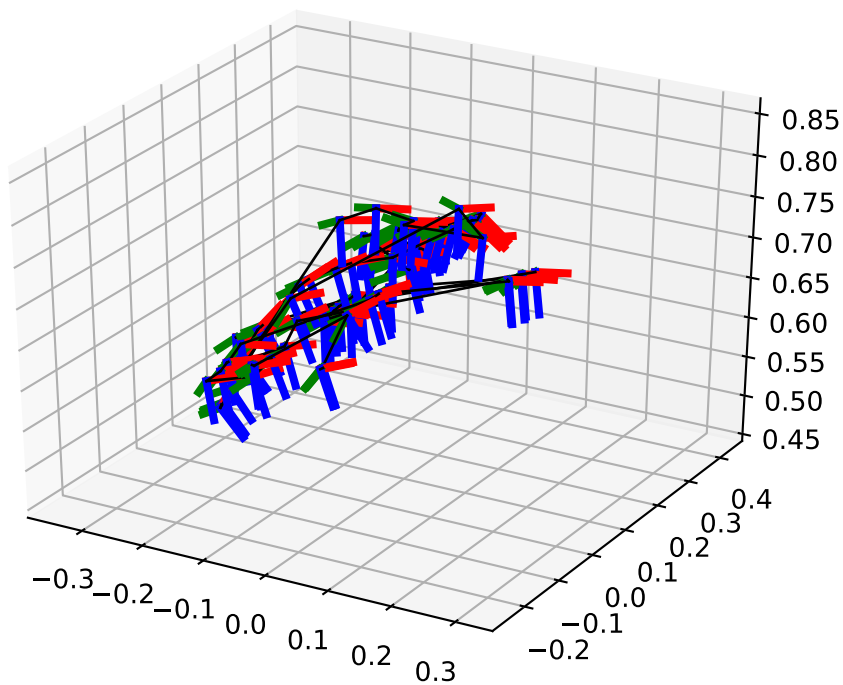
Inter-camera observations graph (edge weight=#mutual obs.)



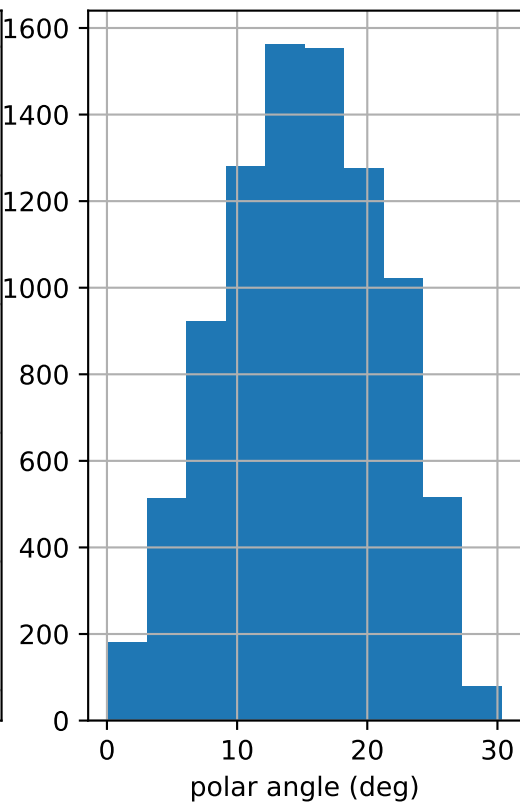
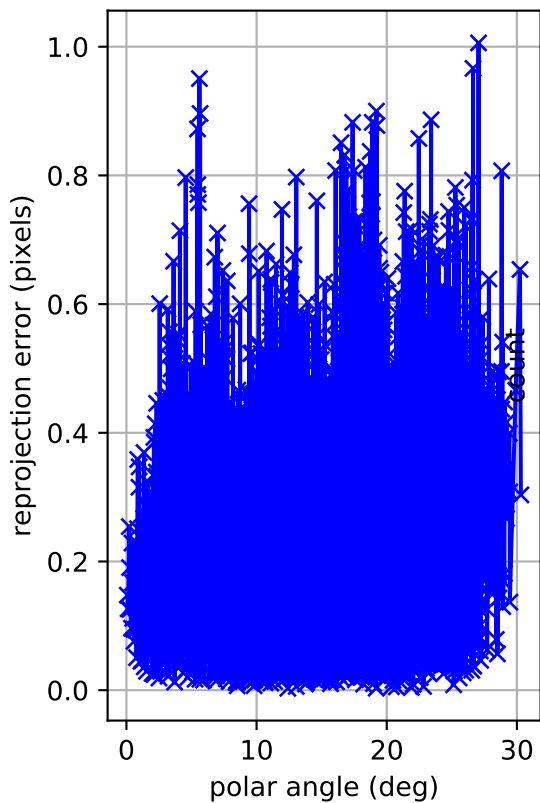
camera system



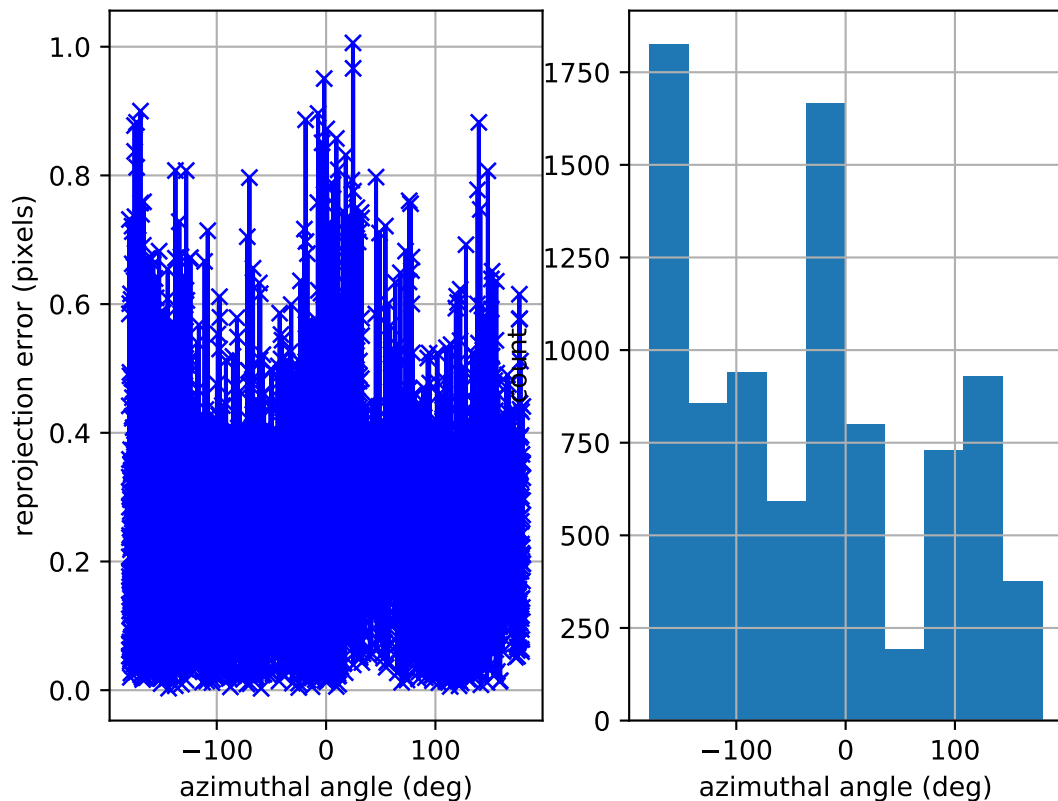
cam0: estimated poses



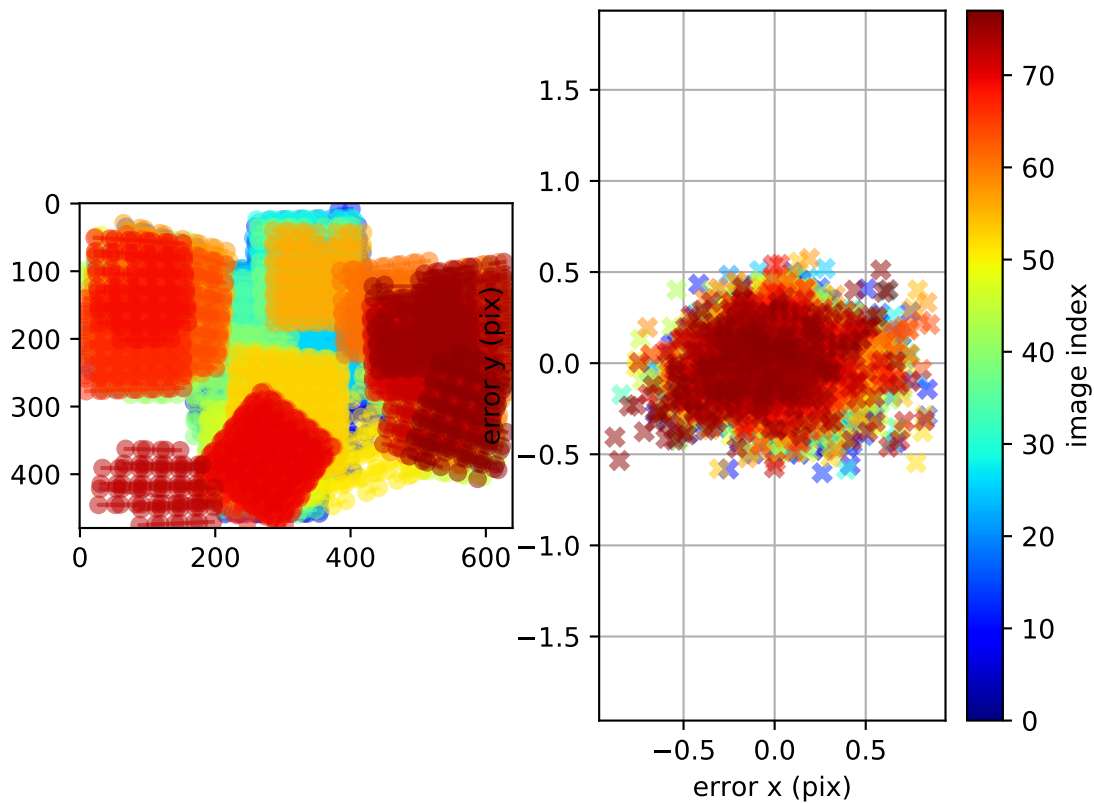
cam0: polar error



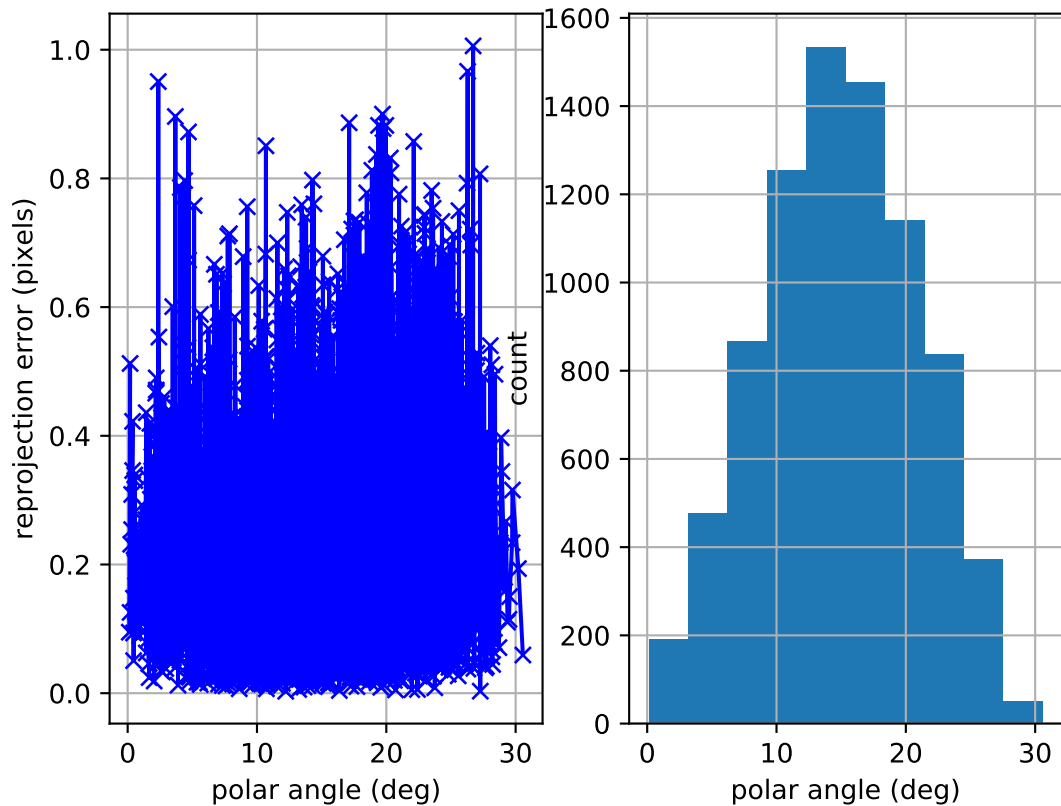
cam0: azimuthal error



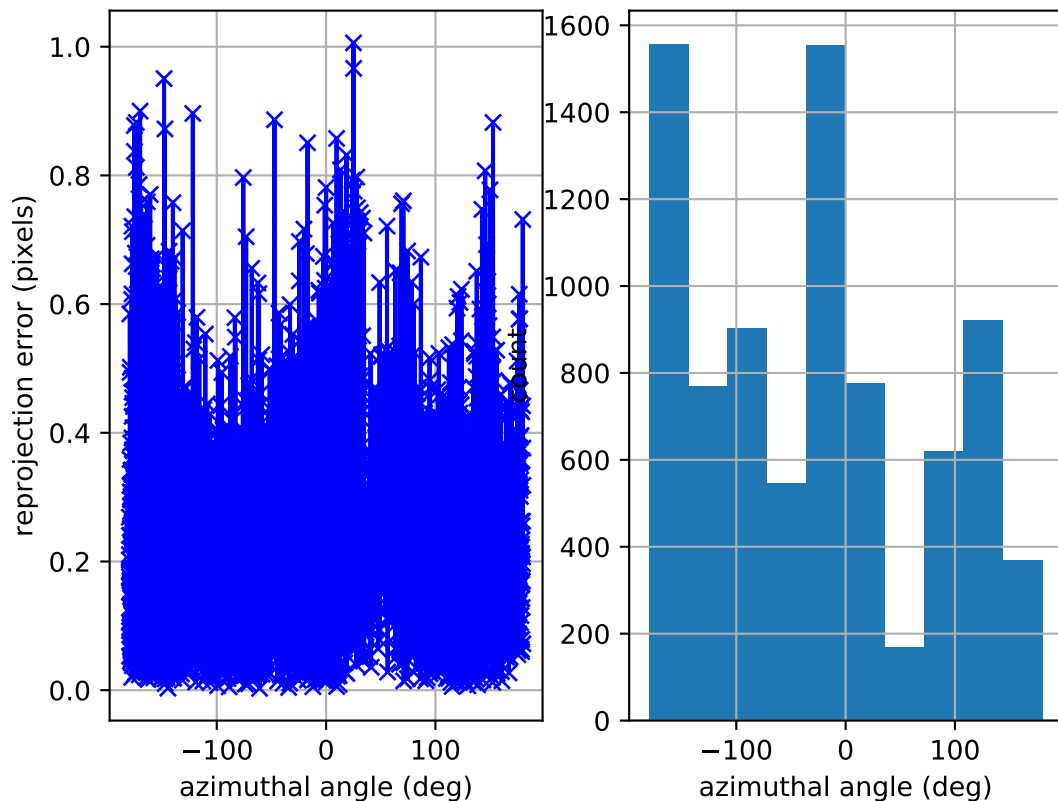
cam0: reprojection errors



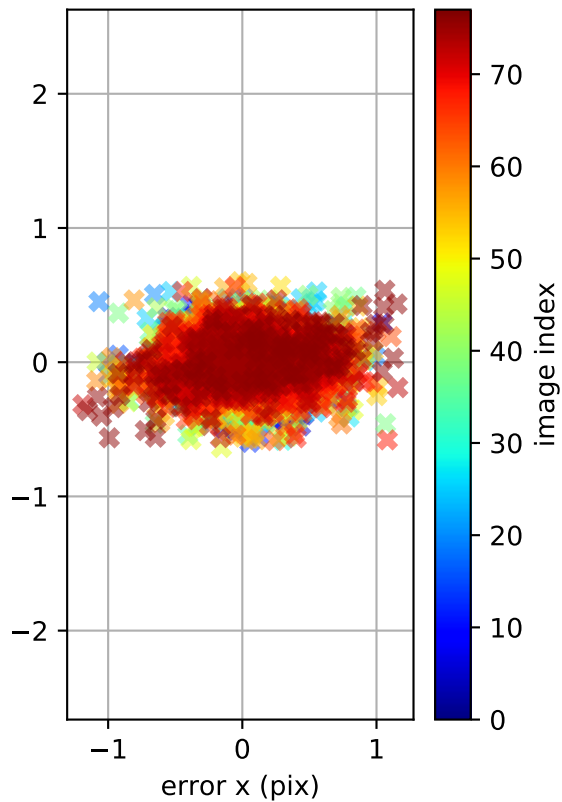
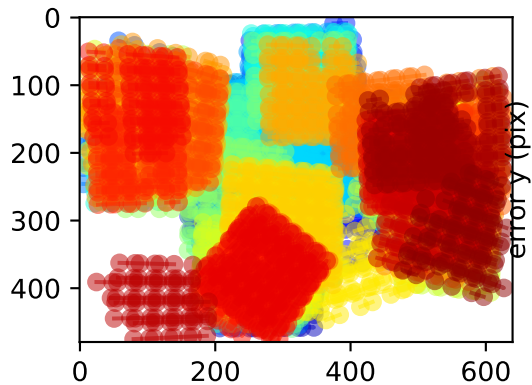
cam1: polar error



cam1: azimuthal error

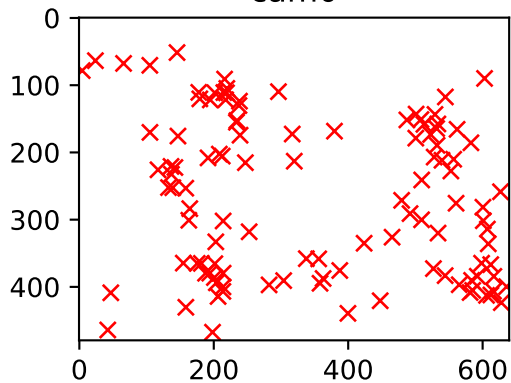


cam1: reprojection errors



Location of removed outlier corners

cam0



cam1

