

Calibration results

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Camera-system parameters:

cam0 (/left):

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

distortion: [0.00055639 -0.00401265 -0.0014965 0.00002674] +- [0.00656078 0.00876682 0.00043401 0.00105312]

projection: [392.65059154 393.06522512 323.2957017 240.73955641] +- [0.18302209 0.1935856 0.01006809 0.00026555]

reprojection error: [-0.000007, 0.000014] +- [0.051053, 0.059353]

cam1 (/right):

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

distortion: [0.00218925 -0.00893799 -0.00079582 -0.00033049] +- [0.0031419 0.00516424 0.00056645 0.00049004]

projection: [391.42985643 391.83822905 323.97537324 241.07201705] +- [0.18522369 0.18473271 0.46614983 0.80073868]

reprojection error: [-0.000043, 0.000016] +- [0.100435, 0.103555]

cam2 (/color):

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

distortion: [-0.0577825 0.05961862 -0.00092444 -0.00003376] +- [0.00371462 0.0088957 0.00050908 0.00043026]

projection: [385.10093578 385.18686397 325.55430762 243.79459847] +- [0.18779453 0.19223114 0.47364099 0.80147365]

reprojection error: [0.000017, 0.000018] +- [0.099426, 0.095979]

baseline T_1_0:

q: [-0.00285995 0.0016422 0.00088743 0.99999417] +- [0. 0. 0.]

t: [-0.03304321 -0.00001081 0.0009496] +- [0. 0. 0.]

baseline T_2_1:

q: [0.00328352 -0.00191657 -0.00091294 0.99999236] +- [0.00136263 0.00187327 0.00014947]

t: [0.03607324 0.00014605 -0.00008709] +- [0.00008353 0.00008072 0.0003183]

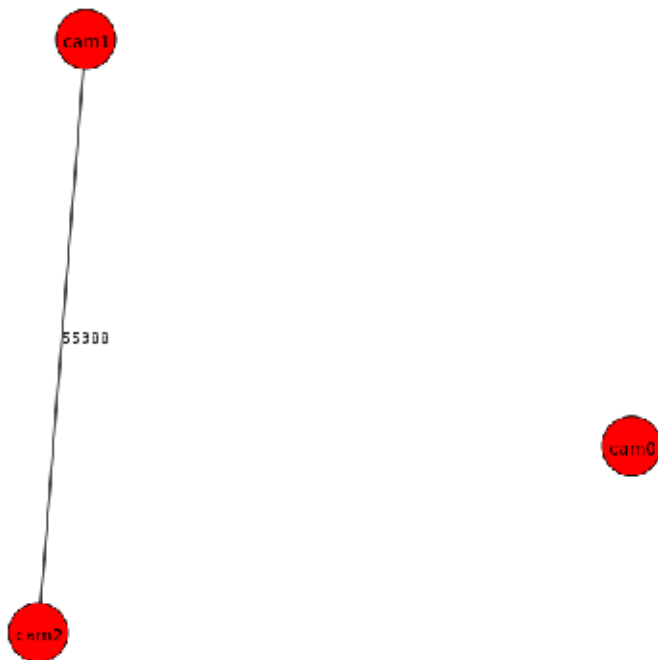
Target configuration

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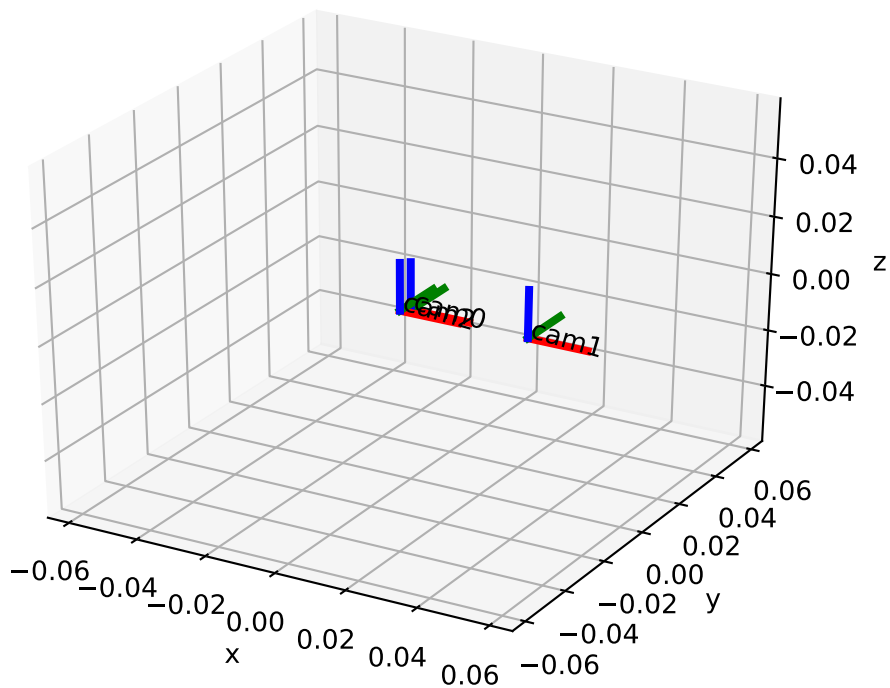
Type: aprilgrid

Tags:
Rows: 6
Cols: 6
Size: 0.022 [m]
Spacing 0.0066 [m]

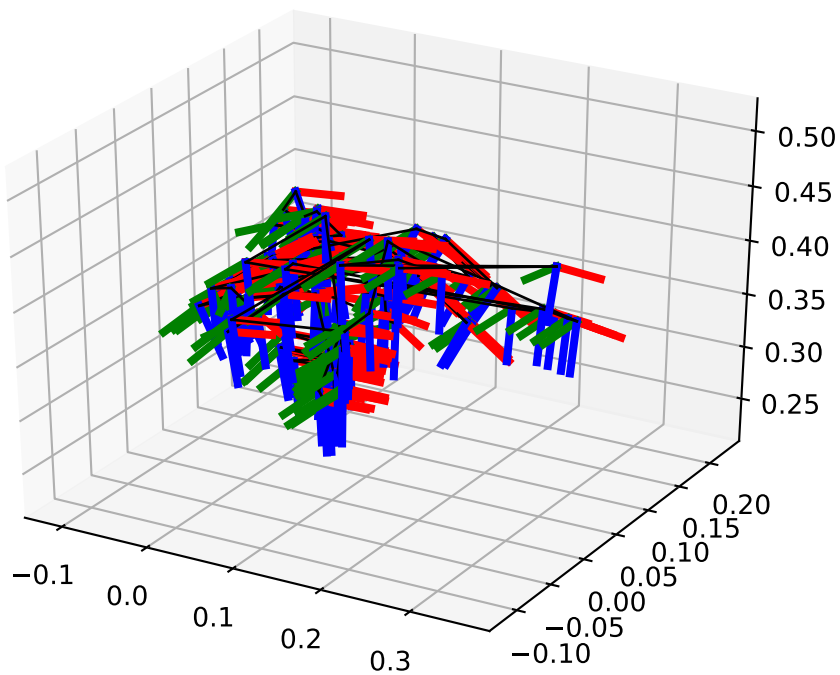
Inter-camera observations graph (edge weight=#mutual obs.)



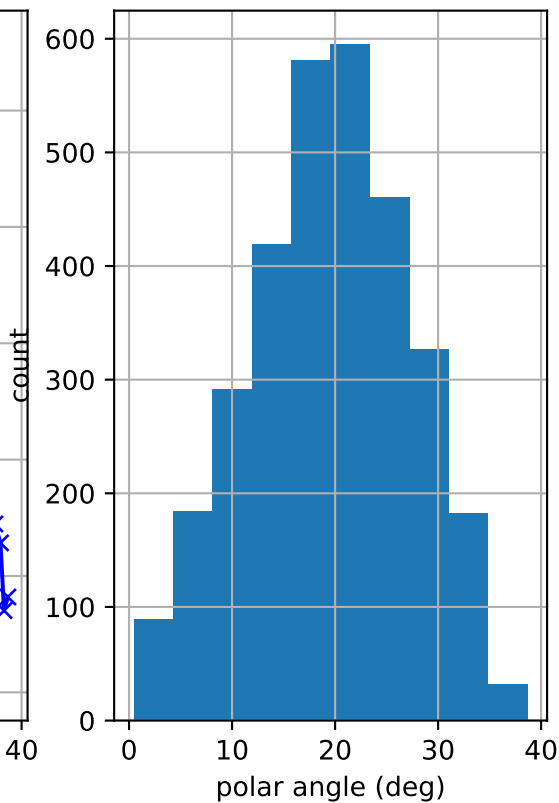
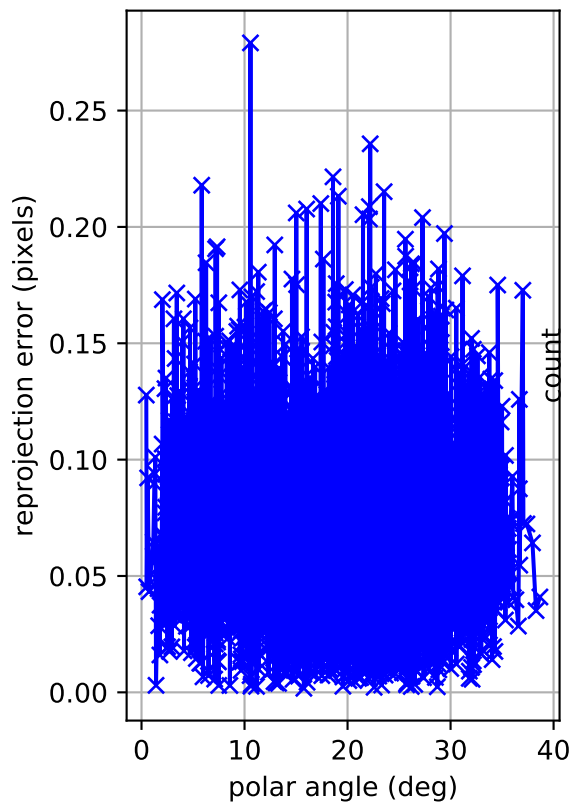
camera system



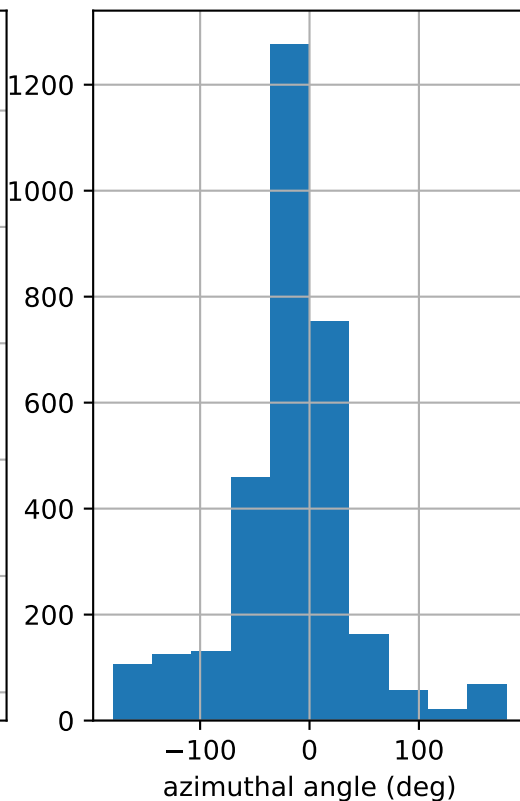
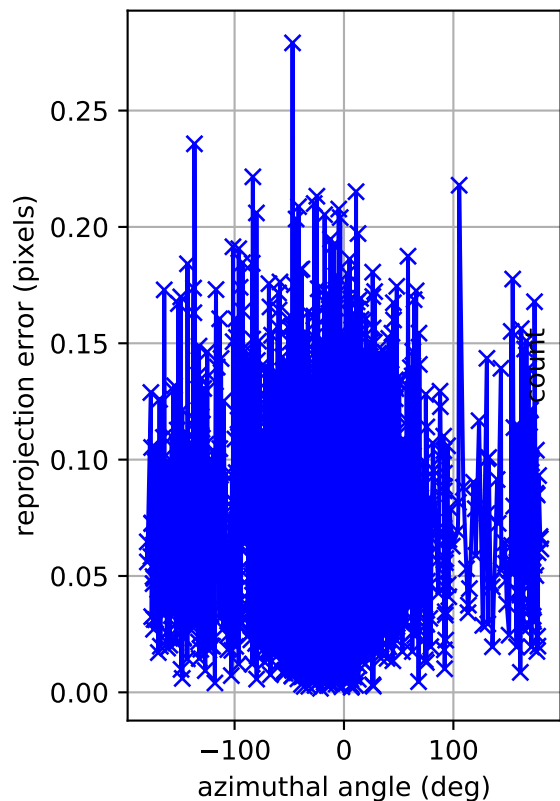
cam0: estimated poses



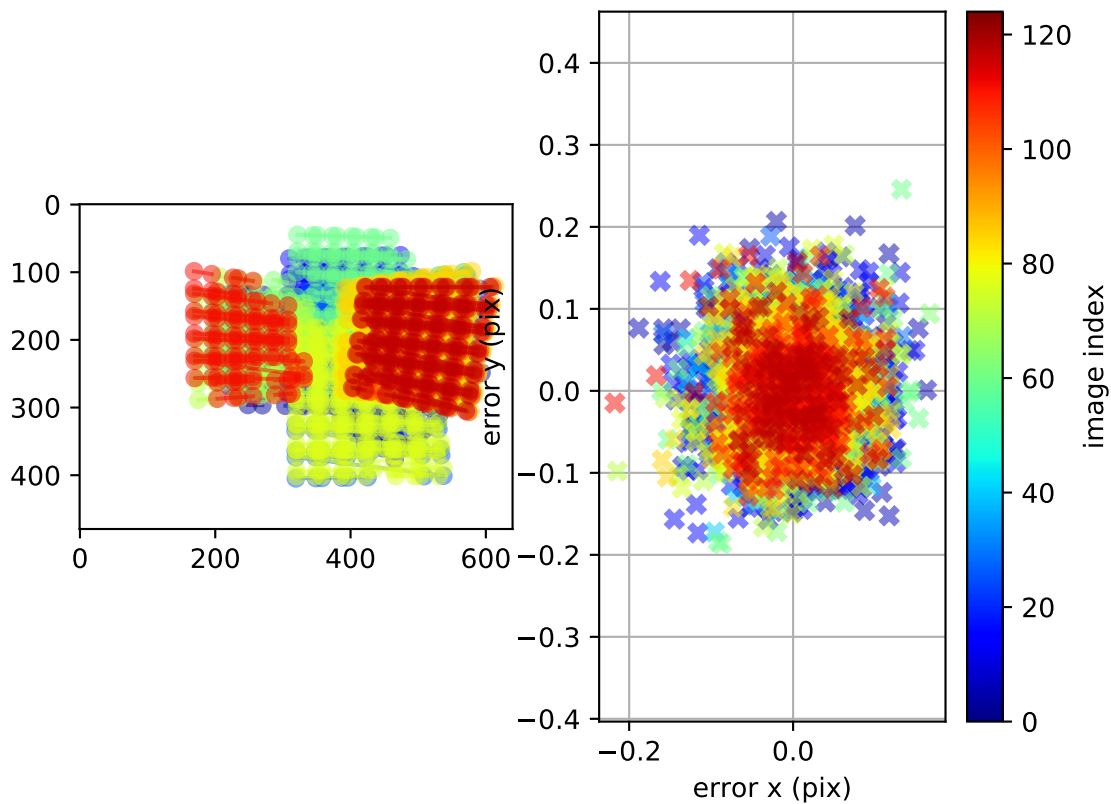
cam0: polar error



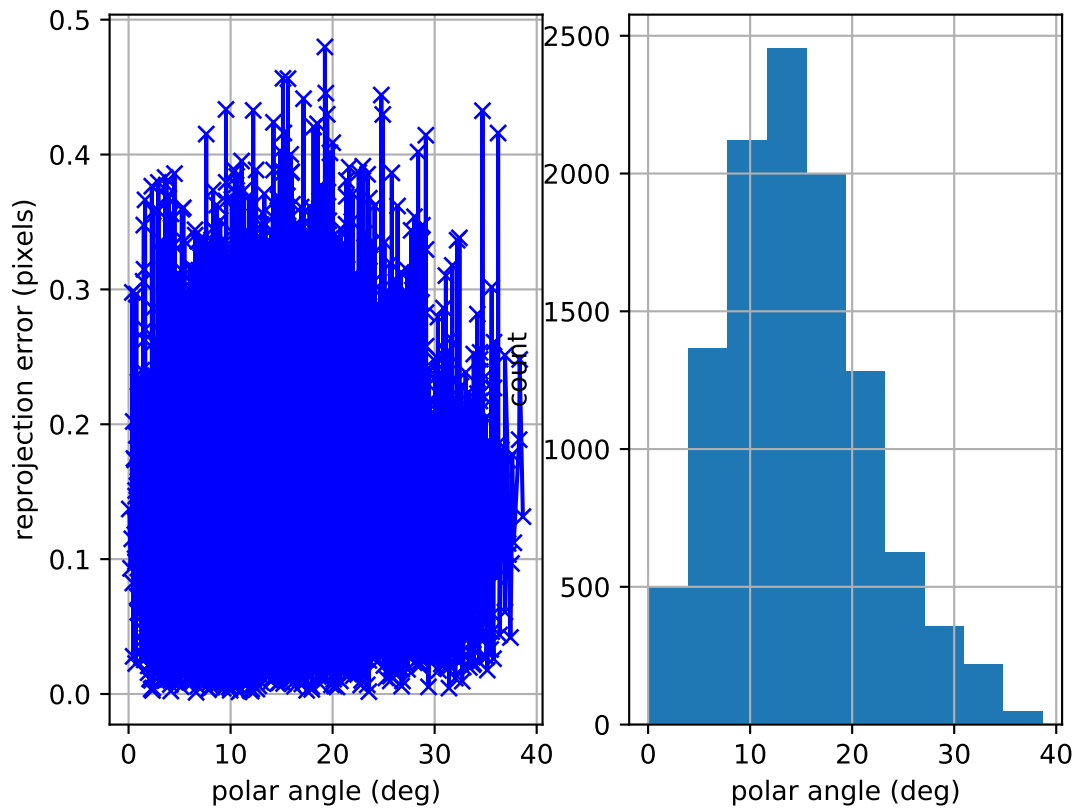
cam0: azimuthal error



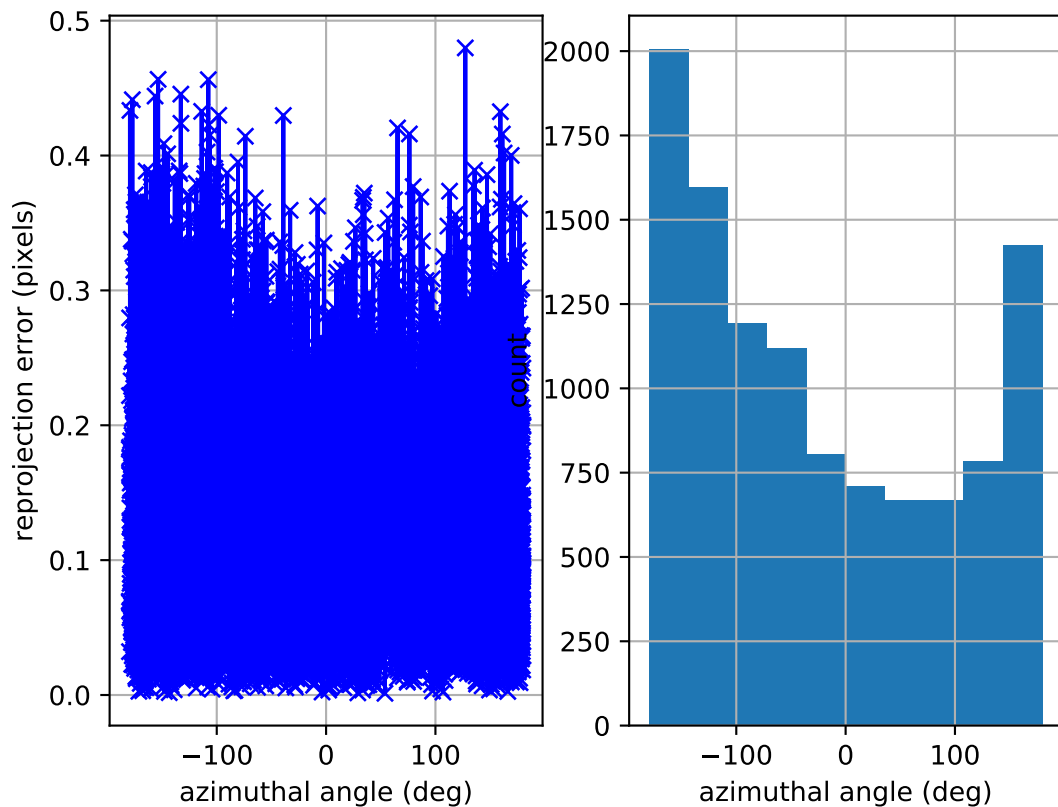
cam0: reprojection errors



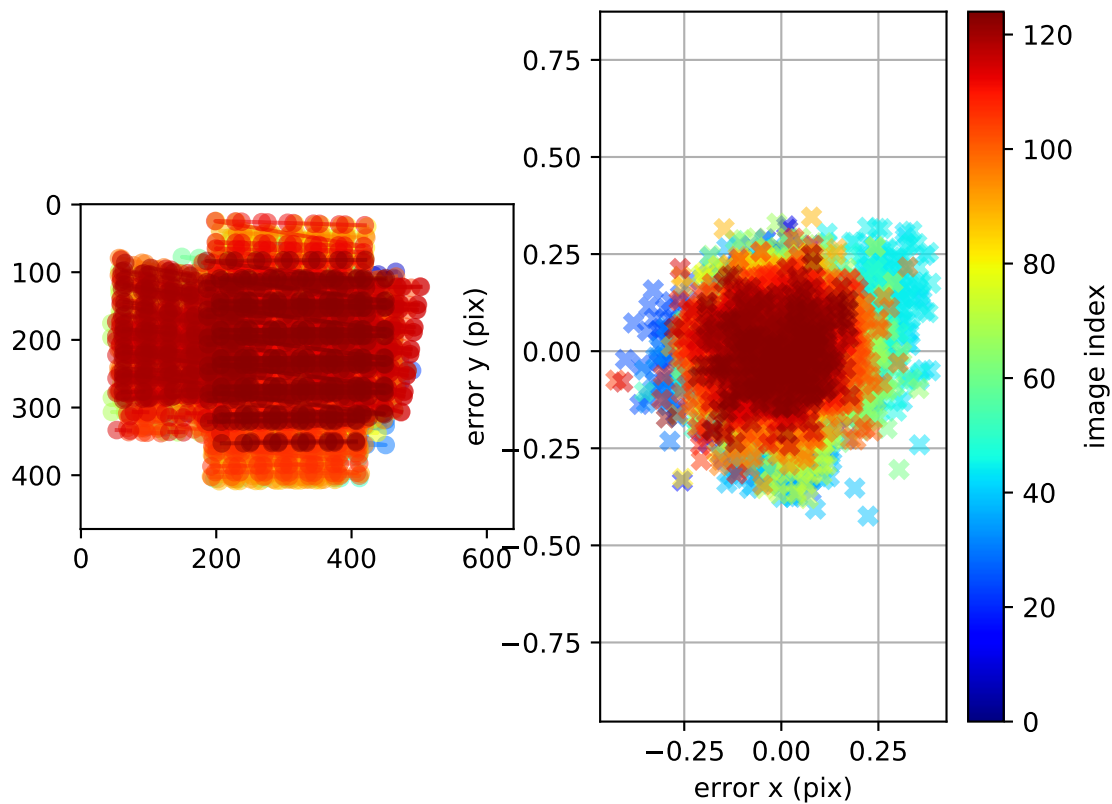
cam1: polar error



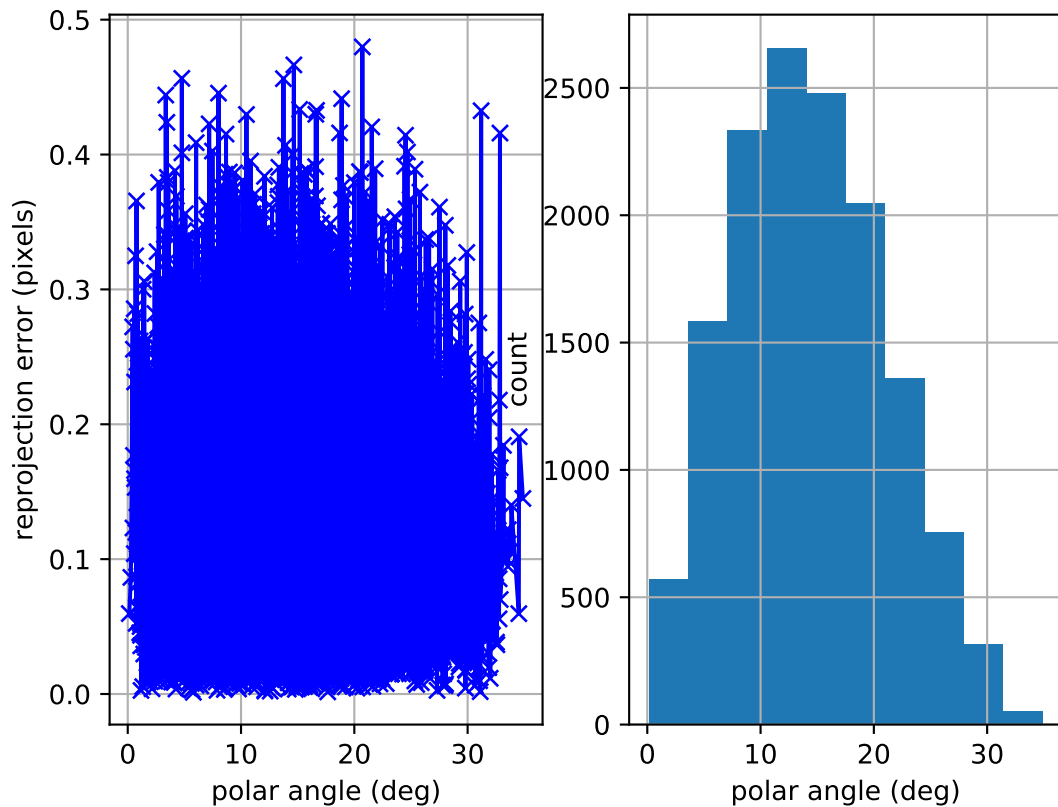
cam1: azimuthal error



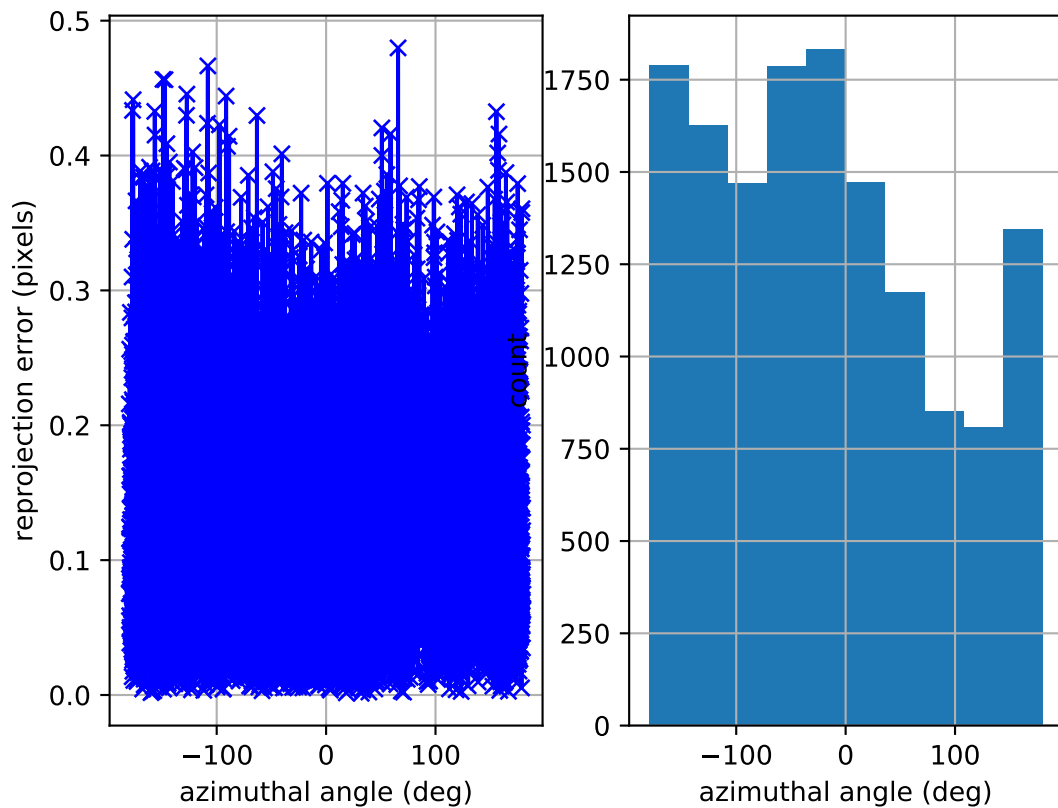
cam1: reprojection errors



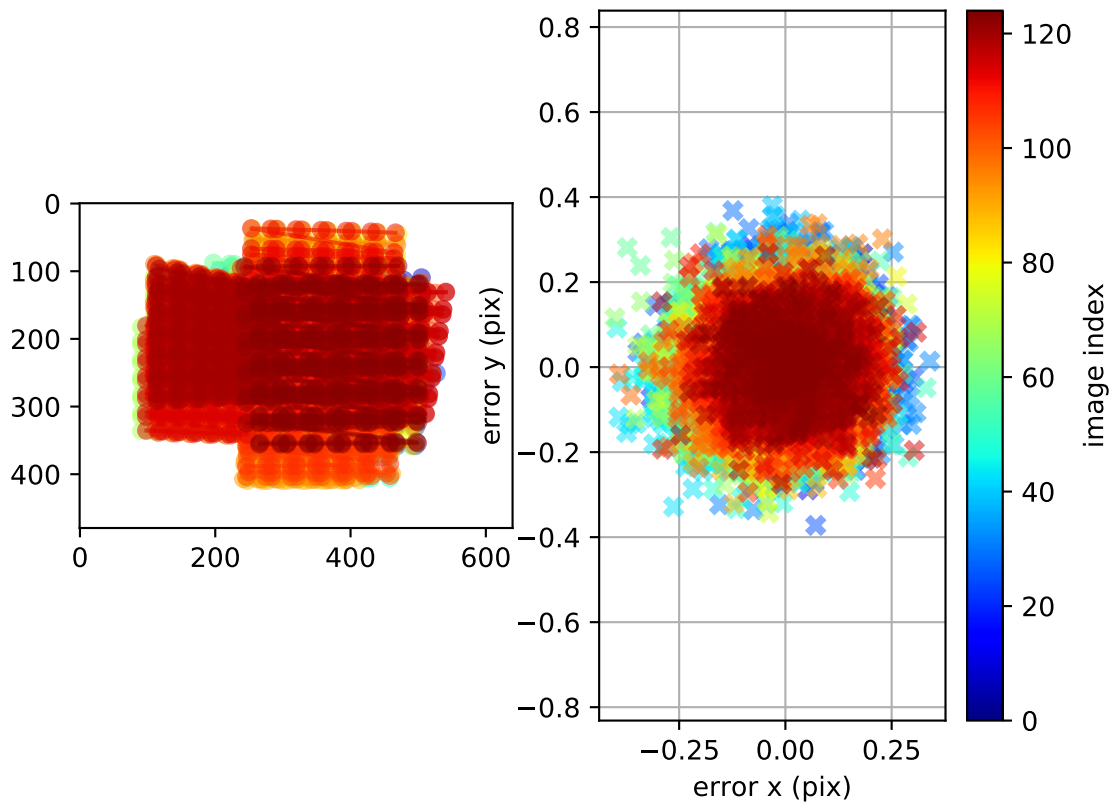
cam2: polar error



cam2: azimuthal error

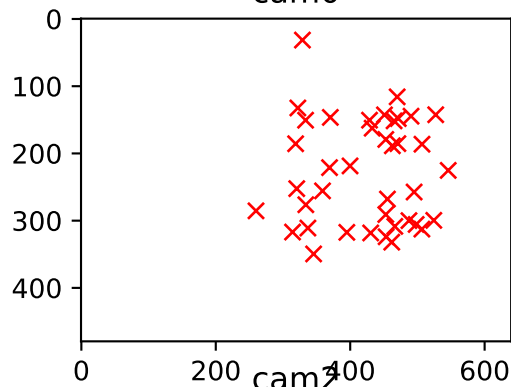


cam2: reprojection errors

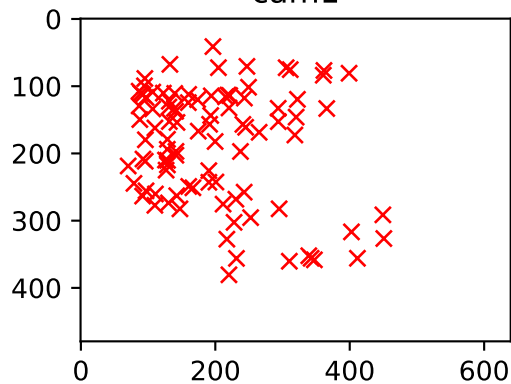


Location of removed outlier corners

cam0



cam1



cam2

