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Optor Cam2pc Visual-Inertial SLAM

SKU 101990260   Read all reviews

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Description

Optor Visual Inertial Camera is a general vision sensor designed for visual algorithm developers.Providing abundant hardware control interface and data interface aimed to reduce development threshold with reliable image and inertial data.

Hardware Specifications

- Physical Dimensions

- Camera Coordinate System between Left camera and IMU

The coordinates of the IMU packaging center in the "left cmos coordinate system":
x=70.14mm±0.06mm
y=-7.38mm±0.06mm
z=-1.4±0.04mm

Left Camera coordinate system
Origin: CMOS sensor array center (image center)

Front

- Hardware Performance and Specifications

	CMOS	IMU
Type	MT9V034	MPV-6050
Exposure Mode	Global shutter	-
Controller IC	CY68013	STM-32
FPS	24-65fps	200fps
Supported Resolution	320*240/640*480/752*480	-
Firmware Update	Firmware Update Supported By Windows Software	-
Baseline	10cm	-
Lens physical interface	M12 Lens interface	-
Lens Specifications	2.1mm/150º+6mm/60º	-
Data interface	Usb 2.0	
Data Delay	(1/Current_FPS)s	100us
Frame Synchronization	Stereo Synchronization Triggered By Camera Driver	-

Product Feature

- IMU zero bias calibration program, Zero bias initialization algorithm of DMP, High precision 6-DOF data, Minimum attitude drift.
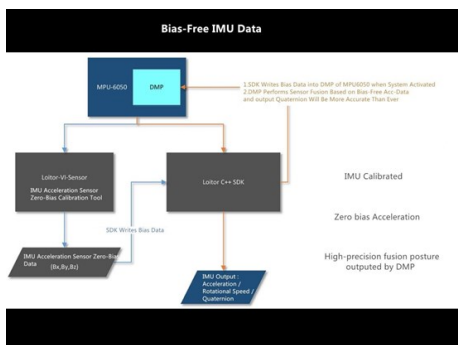
- Stereo optical parameters already accurately calibrated
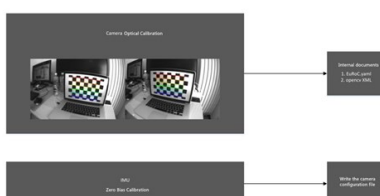
- The lens seat rifled through special processing, to ensure the camera would not loosen in the long-term delivery and the lens can be replaced.

- SDK needs no compilation,no special dependency libraries(only relay on libusb)

- stable and reliable ROS driver

- Ubuntu 16/14 supported

Technical Details

Dimensions0mm x 0mm x 0mm
Weight   G.W 140g
Battery   Exclude

Part List

Camera Module1
usb cable   1

ECCN/HTS

ECCN   ERA99
HSCODE9031809090

Documents

Documents

Reviews

January 11,2018 by Anonymous User

Was this review helpful ?

0

Questions and Answers

Have a question about this? Ask people who

0

Is there a working live-cd image? I have not gotten the camera to run, because always something with the drivers does not fit or are not installable.

Drebert.Thomas on Feb 19,2018   Reply   upvote (0)

Hi Drebert~ Unfortunately,we do not have such image.Please follow the guide link below.It will helps you with the driver step by step.Regards. =====================================dividing line=========================== https://github.com/optor-vis/vi-stereo-v1/blob/master/optor_VI_Sensor_SDK_V1.0/Optor%20User%20Manual.pdf

Seeed Techsupport Team on Feb 28,2018 09:46 AM   Reply   upvote (0)

0   How the trajectory and 6DOF been calculated, solely based on IMU or a data fusion of IMU+ camera frame features?

Mary Li on Jun 07,2017   Reply   upvote (0)

Hi Mary~ We only provide the topic data between IMU and the camera.Regards

Seeed Techsupport Team on Feb 28,2018 09:49 AM   Reply   upvote (0)

0

Some questions about synchronization: * "Stereo Synchronization Triggered By Camera Driver" is not really clear to me. How accurate is the sync, what is the max time difference between the cameras? Do the camera's stay in sync or are they only synchronized once (and thus prone to drift)? * Can the IMU data be synced with the camera frames, eg because both the IMU data and the frames have timestamps from the same clock?

helium_2 on Jun 06,2017   Reply   upvote (0)

Hi Remco~ 1.We've not test the time difference between the cameras. 2.Always stay in sync. 3.The IMU data is synced with the camera frames and they have the same clock. Regards

Seeed Techsupport Team on Feb 28,2018 09:53 AM   Reply   upvote (0)

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