

Calibration results

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Camera-system parameters:

cam0 (/camera/front_left/image_raw):

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

distortion: [-0.31230167 0.07057178 0.00184923 0.00801834] +- [0.00126208 0.00051542 0.00013316 0.00059402]

projection: [390.2060154 395.2466301 310.49184871 238.02716134] +- [0.55242442 0.35097369 0.55214465 0.68708279]

reprojection error: [-0.000010, 0.000006] +- [0.382468, 0.290356]

cam1 (/camera/front_right/image_raw):

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

distortion: [-0.30974498 0.06842378 0.0016772 -0.00954168] +- [0.00121402 0.00050326 0.00012854 0.00057584]

projection: [388.75776643 395.63304953 336.20111292 234.25459098] +- [0.55597776 0.35273907 0.56267278 0.68814268]

reprojection error: [0.000153, 0.000003] +- [0.367816, 0.279198]

baseline T_1_0:

q: [0.00174048 0.51802358 -0.00455874 0.85535242] +- [0.00165184 0.00230806 0.00115898]

t: [-0.11559549 -0.00113147 -0.06743359] +- [0.00122582 0.00048352 0.00188532]

Target configuration

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Type: aprilgrid

Tags:

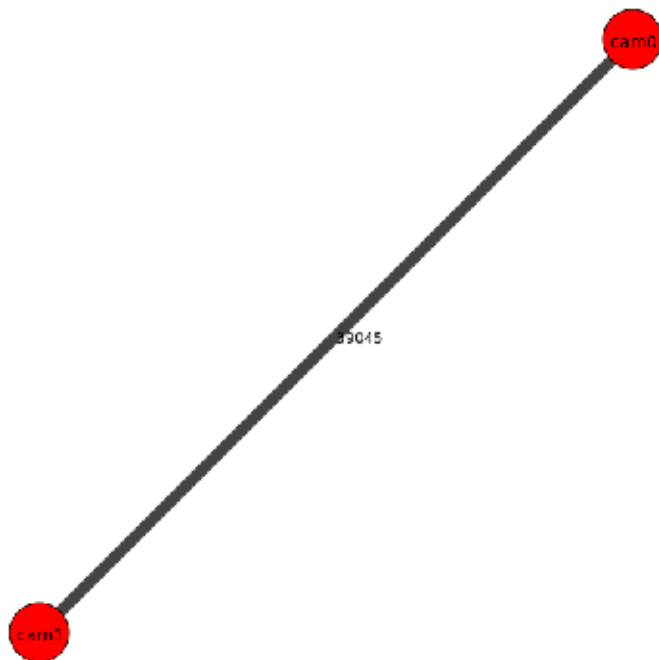
Rows: 6

Cols: 6

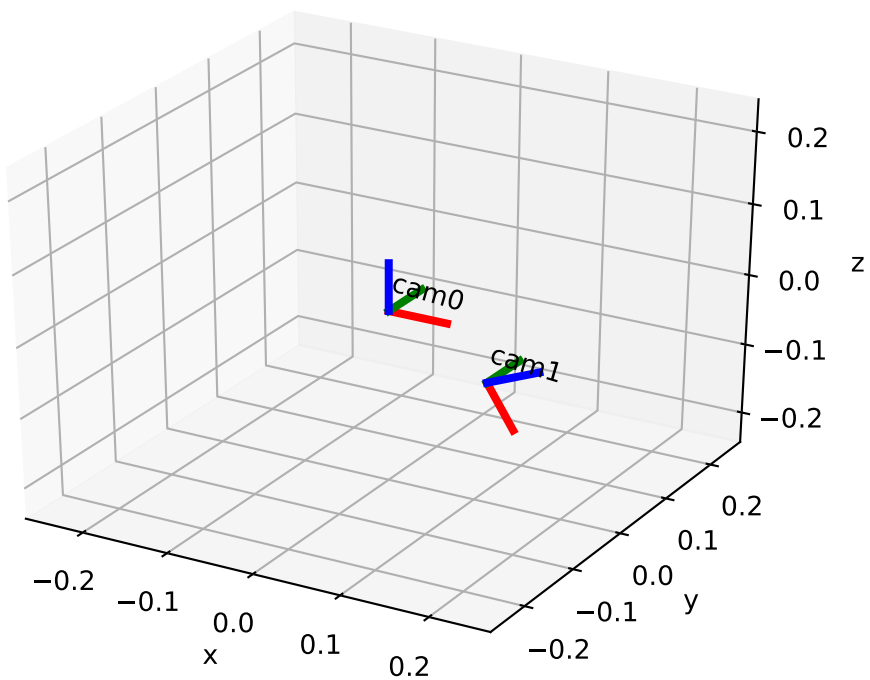
Size: 0.088 [m]

Spacing 0.026399999999999996 [m]

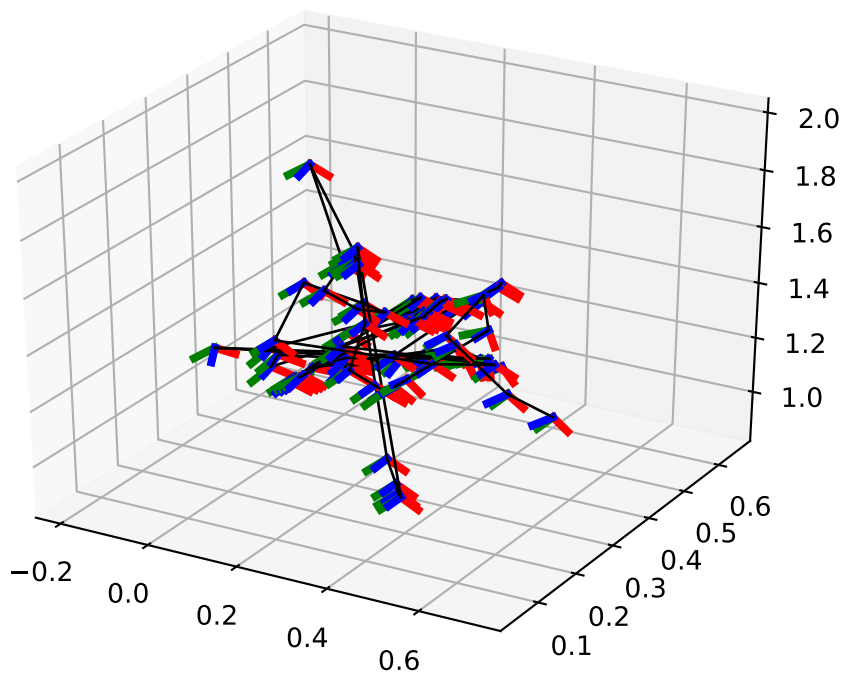
Inter-camera observations graph (edge weight=#mutual obs.)



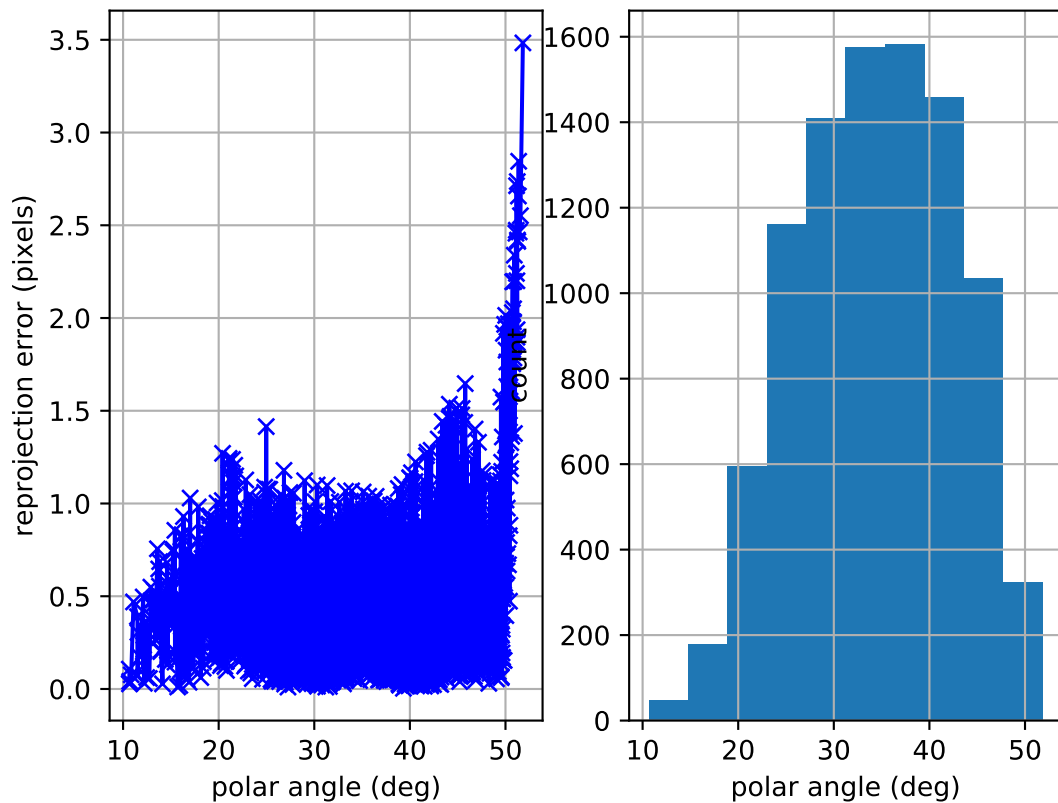
camera system



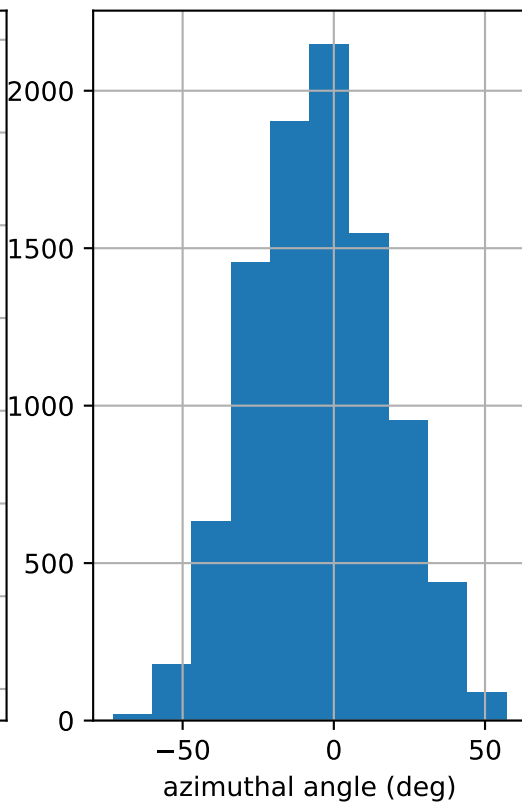
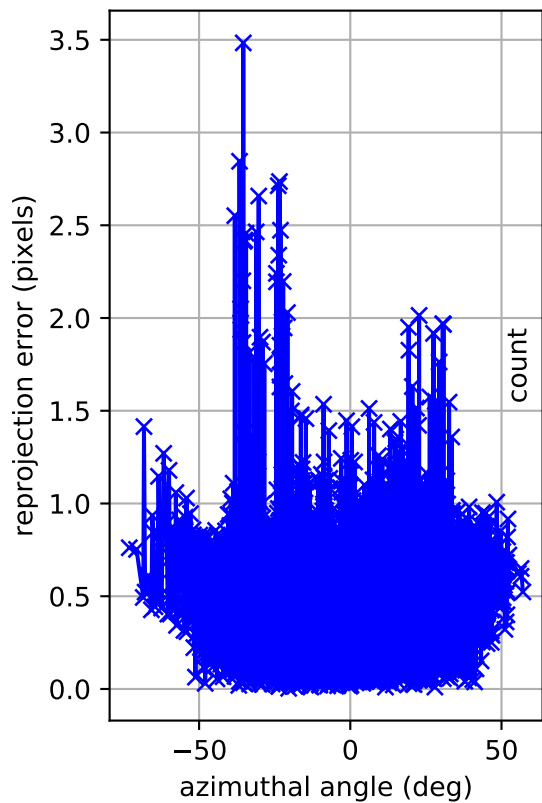
cam0: estimated poses



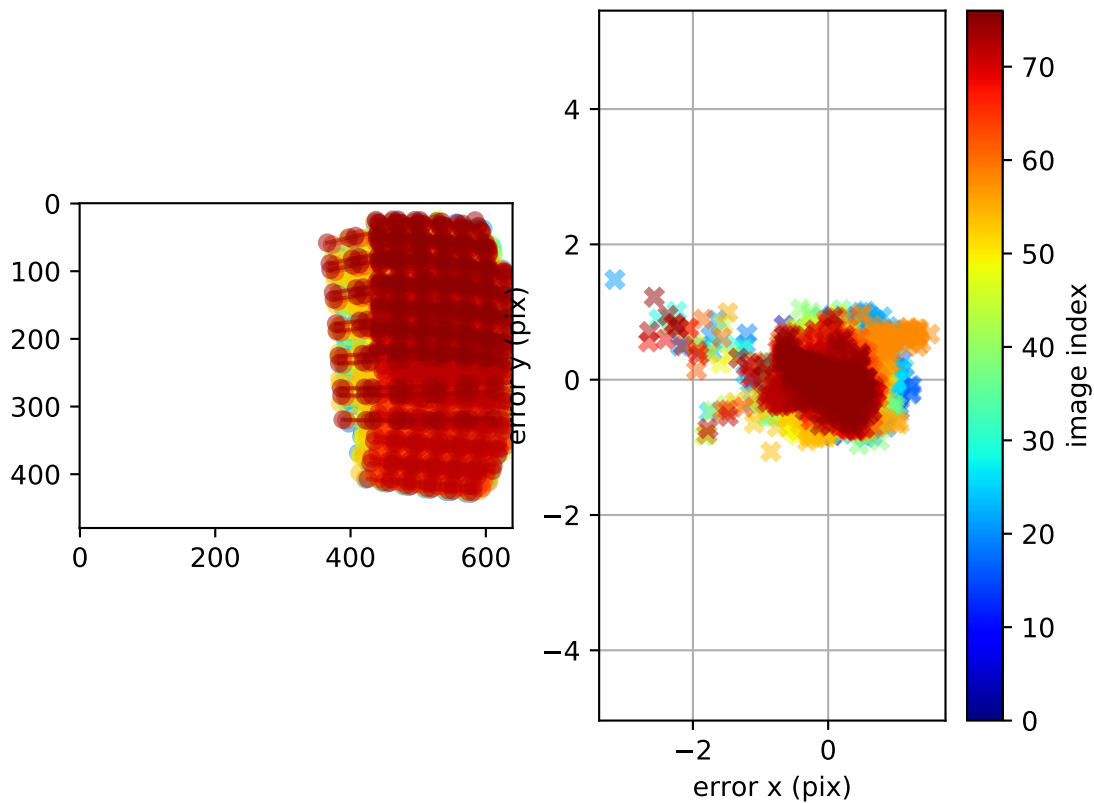
cam0: polar error



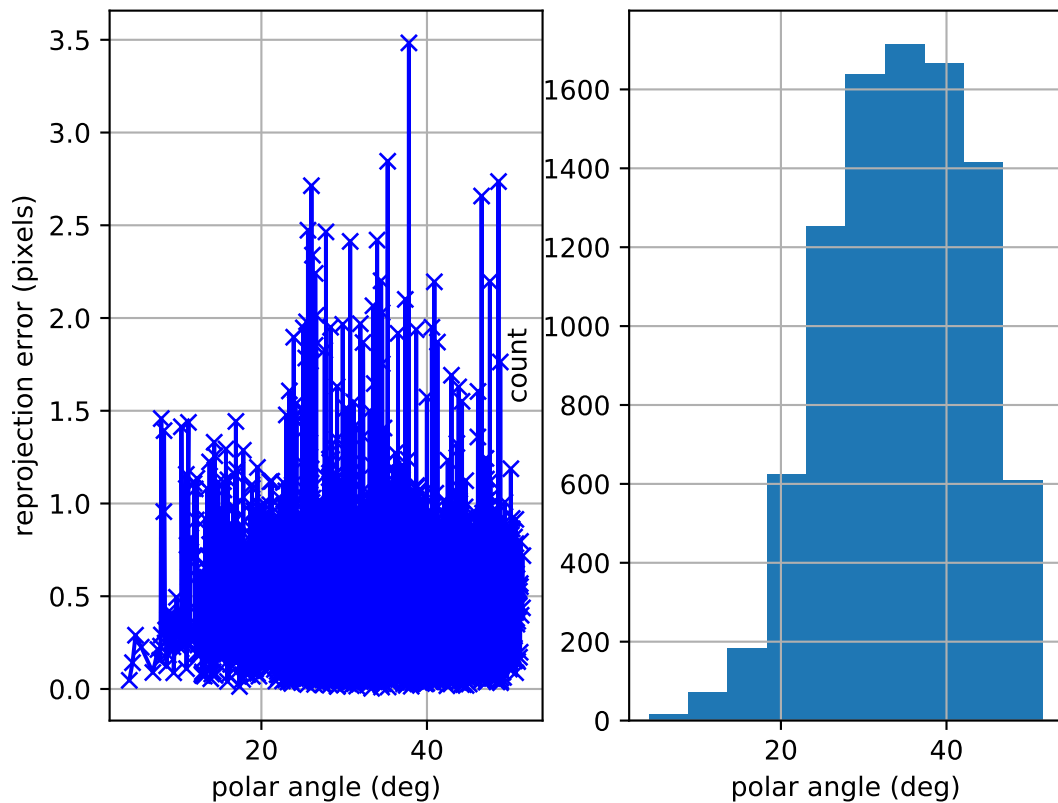
cam0: azimuthal error



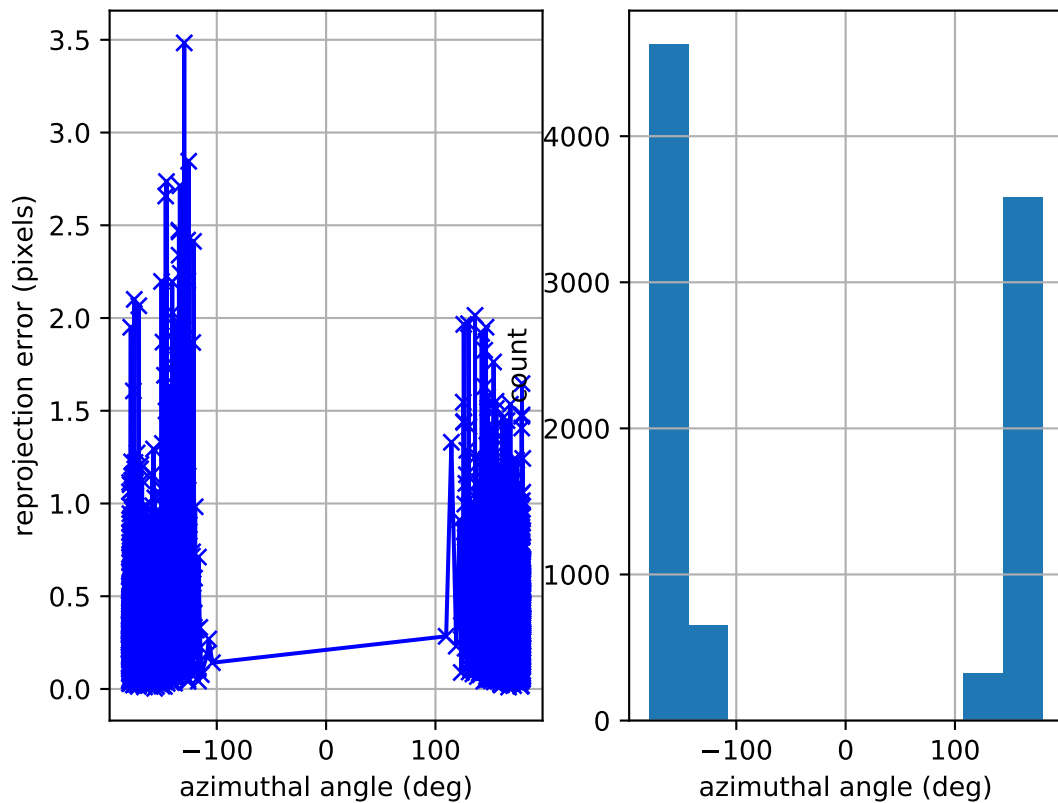
cam0: reprojection errors



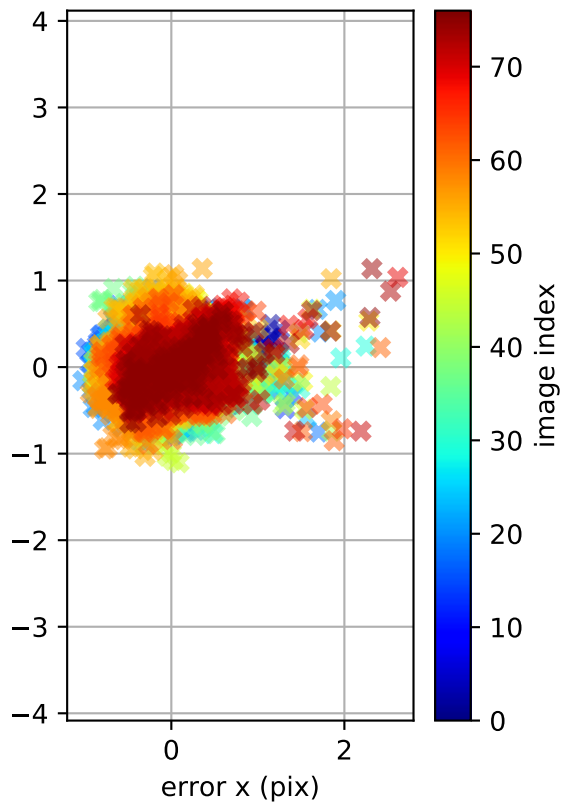
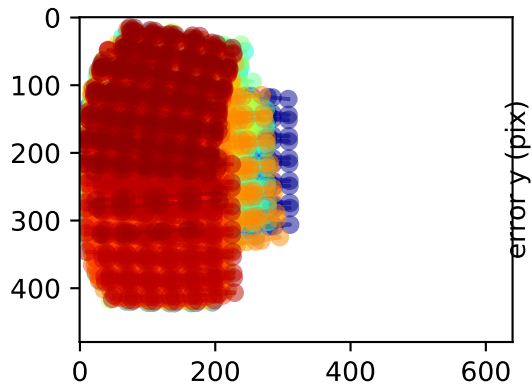
cam1: polar error



cam1: azimuthal error

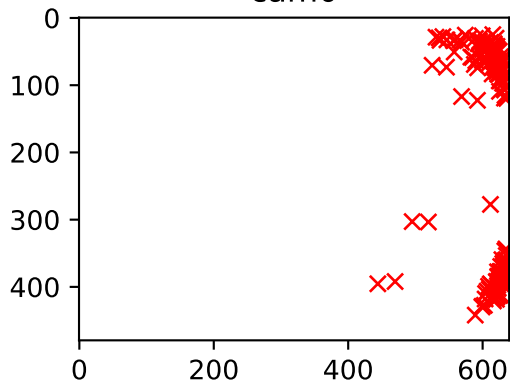


cam1: reprojection errors



Location of removed outlier corners

cam0



cam1

