

Calibration results

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Camera-system parameters:

cam0 (/cam0/image_raw):

type: <class 'aslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>

distortion: [-0.03349987 0.11193092 -0.16808079 0.10395164] +- [0.0134793 0.09134789 0.23600817 0.20336167]

projection: [290.67818866 290.90686424 315.44267788 198.81602372] +- [0.26786864 0.25894271 0.21748954 0.65525955]

reprojection error: [-0.000005, -0.000000] +- [0.091010, 0.094172]

cam1 (/cam1/image_raw):

type: <class 'aslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>

distortion: [-0.02324623 0.03709176 0.03159426 -0.08973974] +- [0.01715485 0.12511819 0.35757161 0.34792307]

projection: [290.86892799 291.20626354 315.86420711 199.70043442] +- [0.23884893 0.22506425 0.22230193 0.55282557]

reprojection error: [0.000005, 0.000000] +- [0.095565, 0.083405]

baseline T_1 0:

q: [0.00210171 0.00679165 0.01198033 0.99990296] +- [0.00189599 0.00145463 0.00018491]

t: [0.08075071 -0.00200075 0.00098398] +- [0.00021696 0.00017053 0.00072638]

Target configuration

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Type: aprilgrid

Tags:

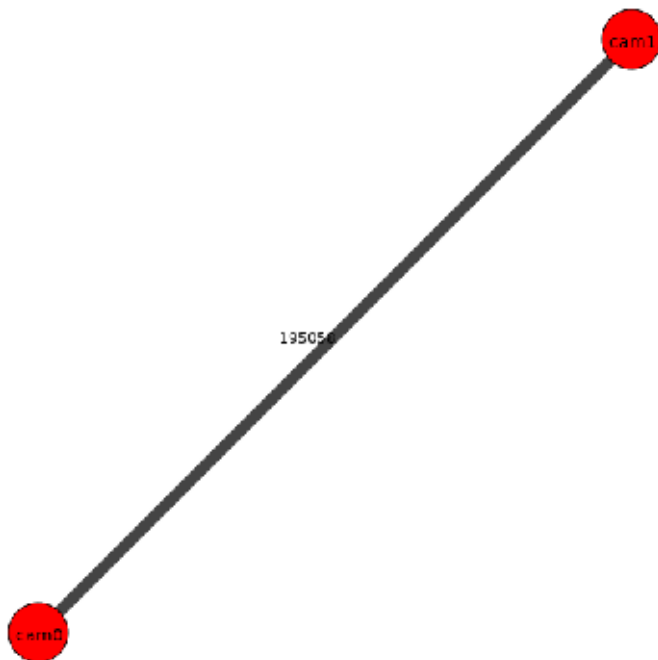
Rows: 6

Cols: 6

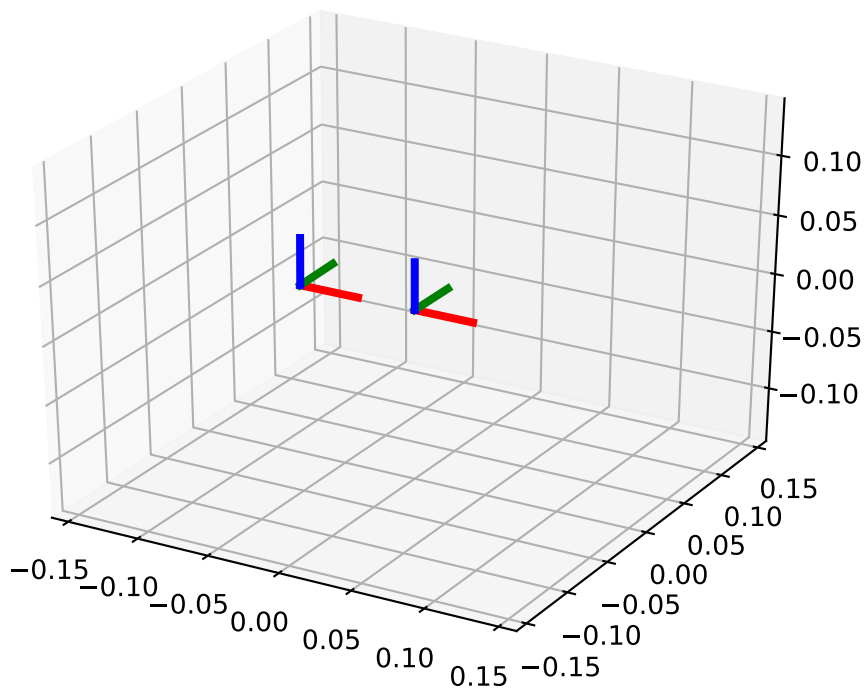
Size: 0.0312 [m]

Spacing 0.00959999976 [m]

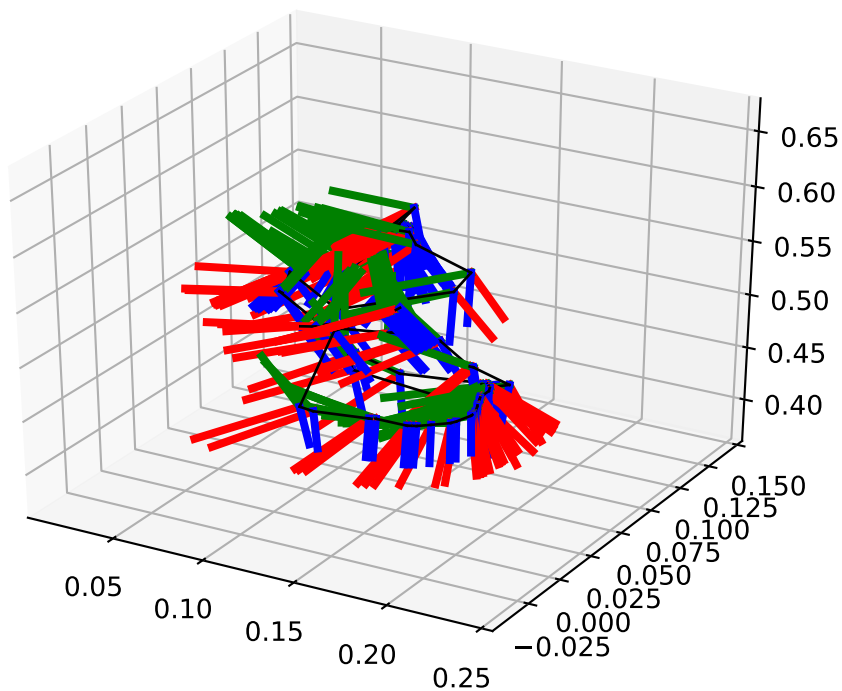
Inter-camera observations graph (edge weight=#mutual obs.)



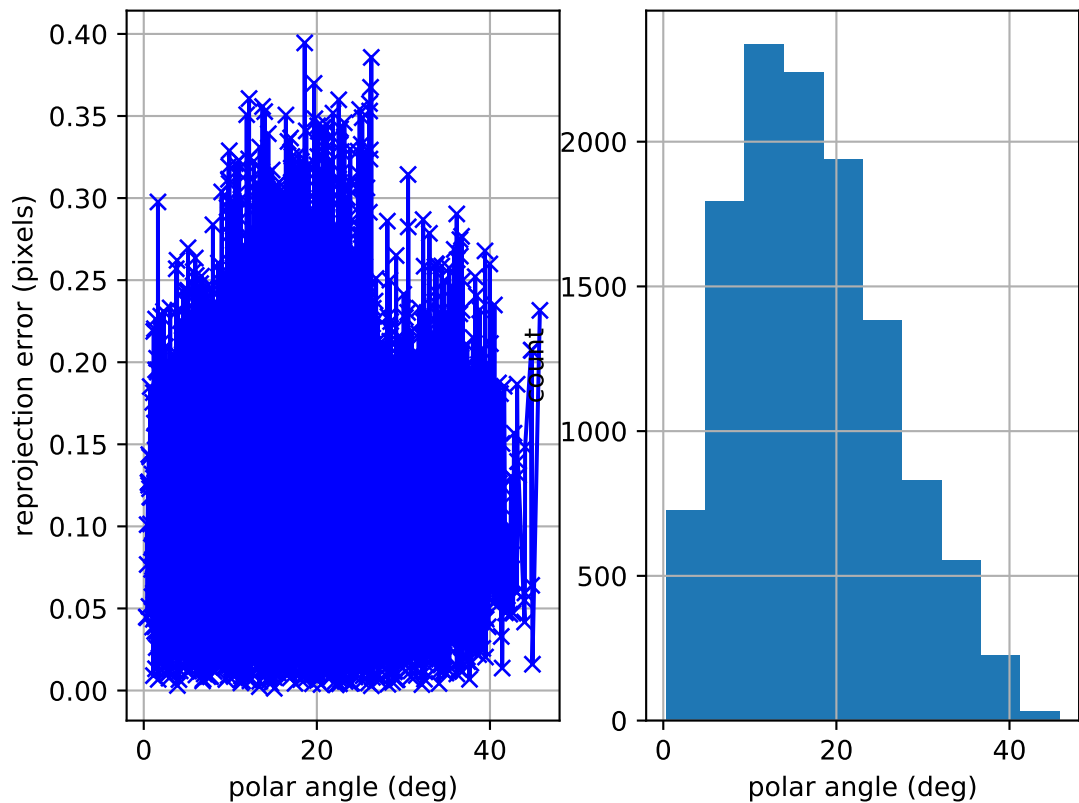
camera system



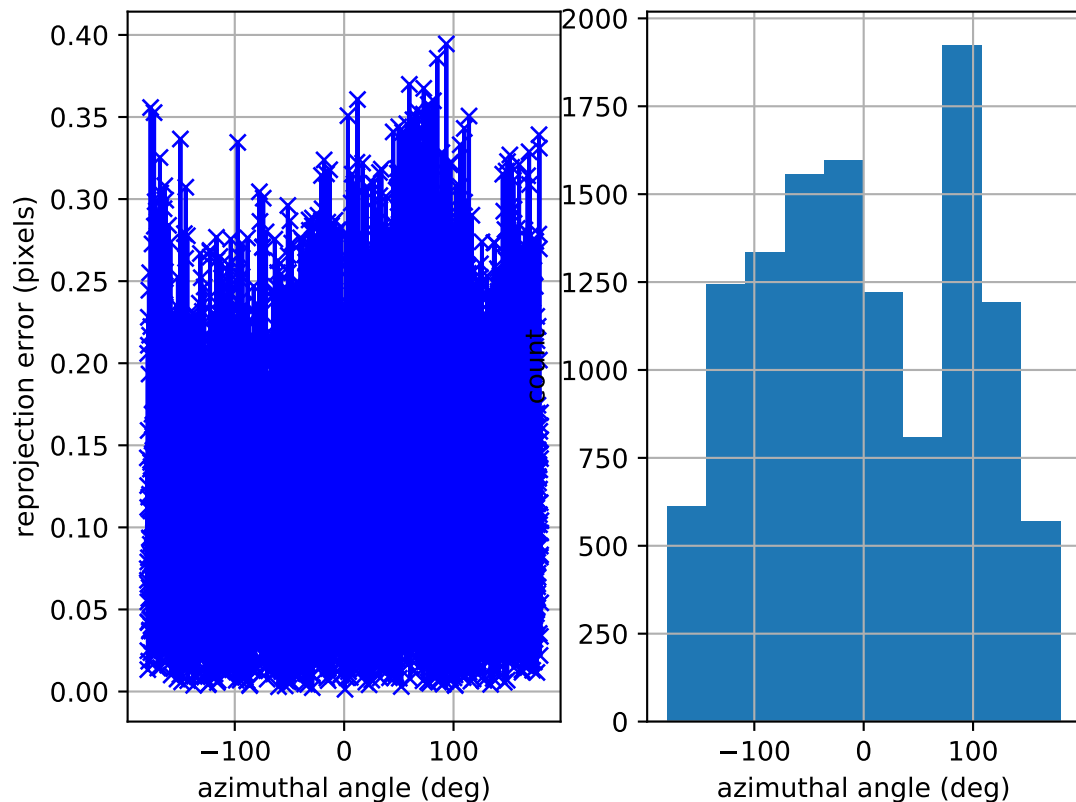
cam0: estimated poses



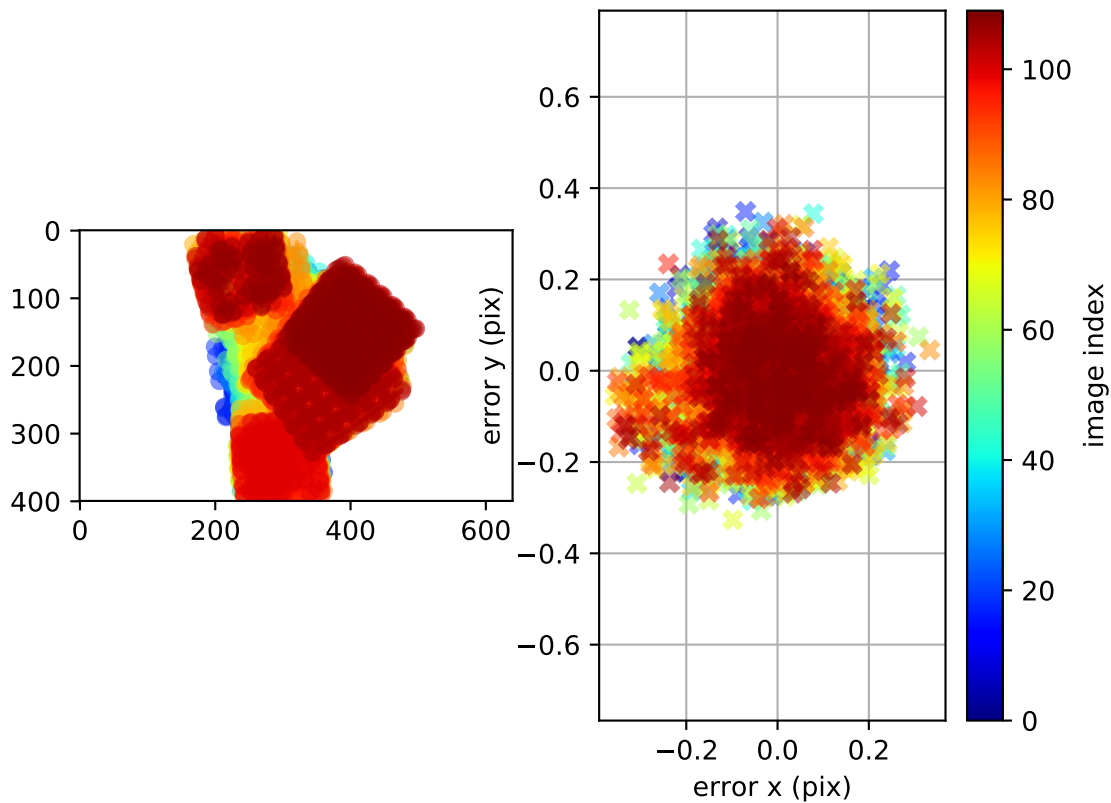
cam0: polar error



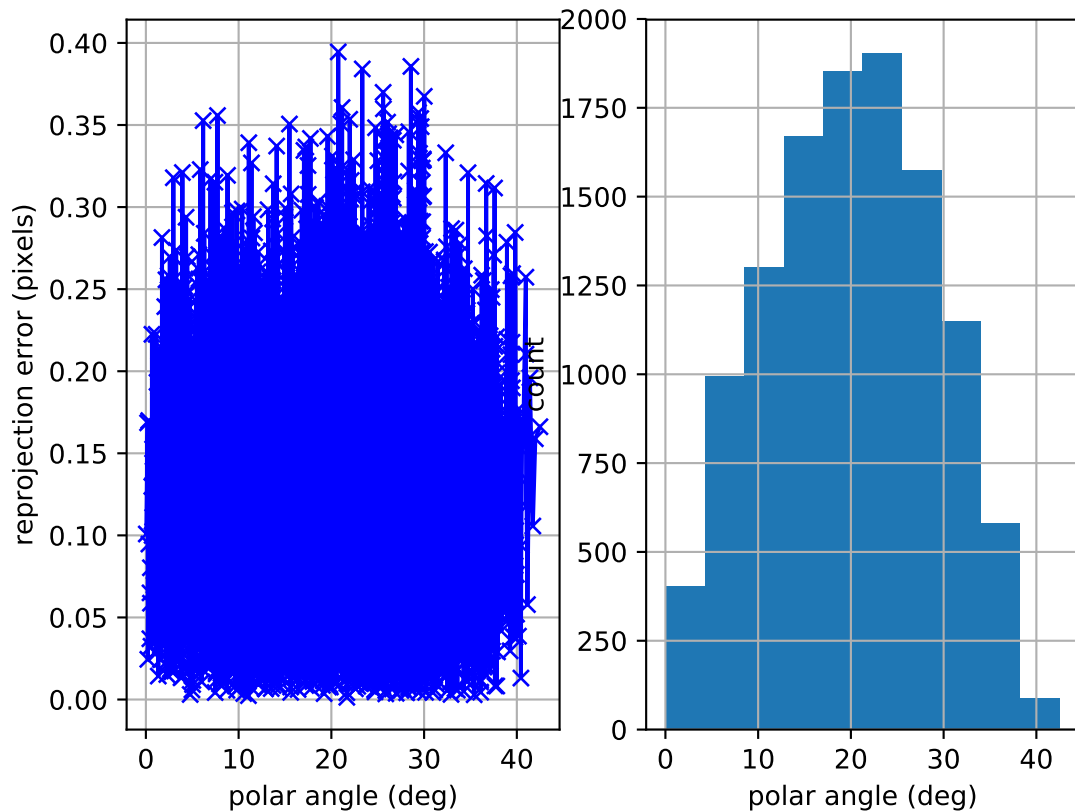
cam0: azimuthal error



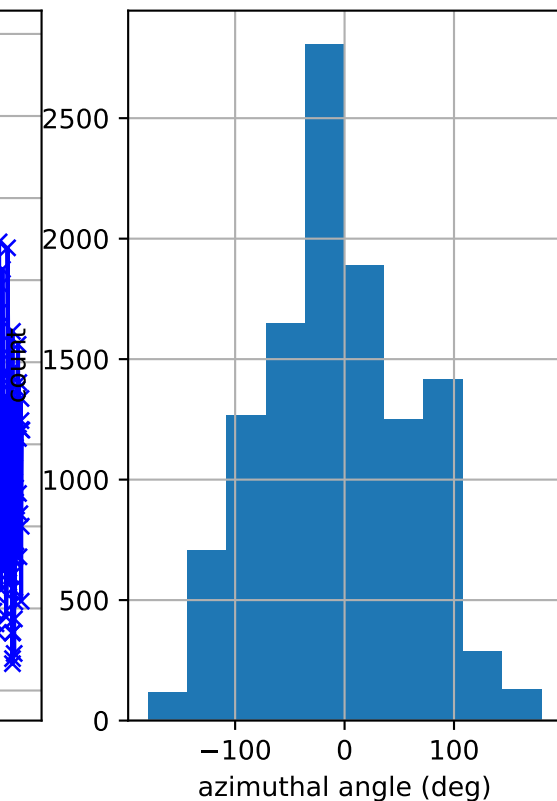
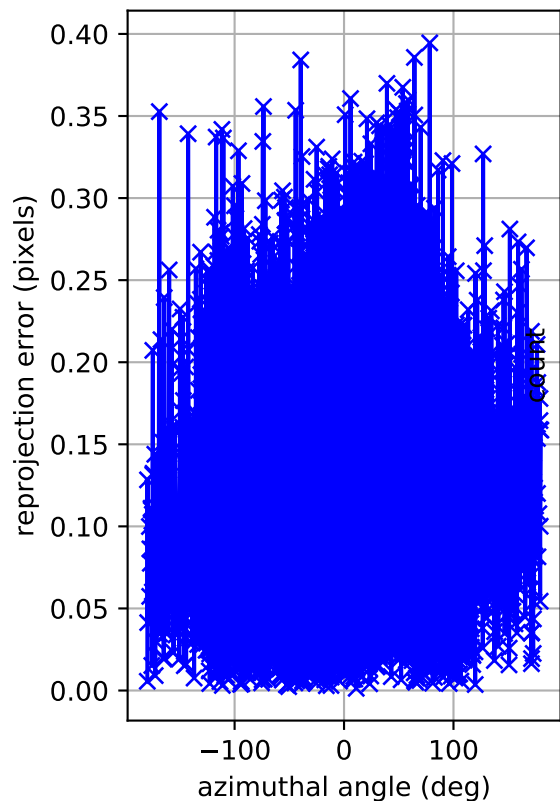
cam0: reprojection errors



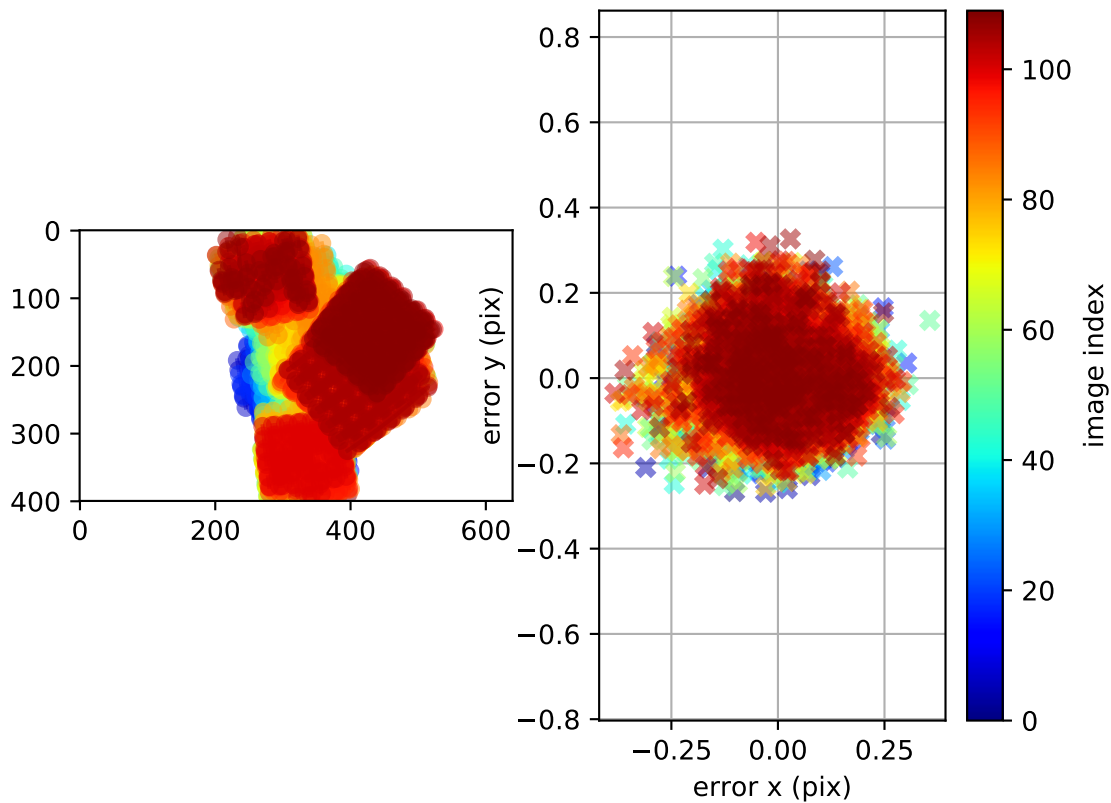
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

