

Calibration results

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Camera-system parameters:

cam0 (/cam0/image_raw):

type: <class 'aslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.33903801 0.10682903 -0.00043748 0.00000848] +- [0.00111822 0.00103151 0.00027066 0.00022384]

projection: [314.06049544 314.87904909 317.25824457 200.75205138] +- [0.20959073 0.20995708 0.45682849 0.50502535]

reprojection error: [-0.000025, -0.000004] +- [0.191993, 0.161931]

cam1 (/cam1/image_raw):

type: <class 'aslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.33596119 0.10377651 -0.00078032 0.00129706] +- [0.00100367 0.00092615 0.0002721 0.00022884]

projection: [314.4249263 315.19791802 313.581654 200.13819589] +- [0.20586815 0.20767764 0.48525207 0.51990054]

reprojection error: [0.000023, -0.000008] +- [0.220178, 0.163634]

baseline T_1_0:

q: [-0.00233643 -0.01148552 -0.01206783 0.99985849] +- [0.00084924 0.00119466 0.00014896]

t: [-0.08048289 -0.00002787 0.00158876] +- [0.00017004 0.00015071 0.00044202]

Target configuration

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Type: aprilgrid

Tags:

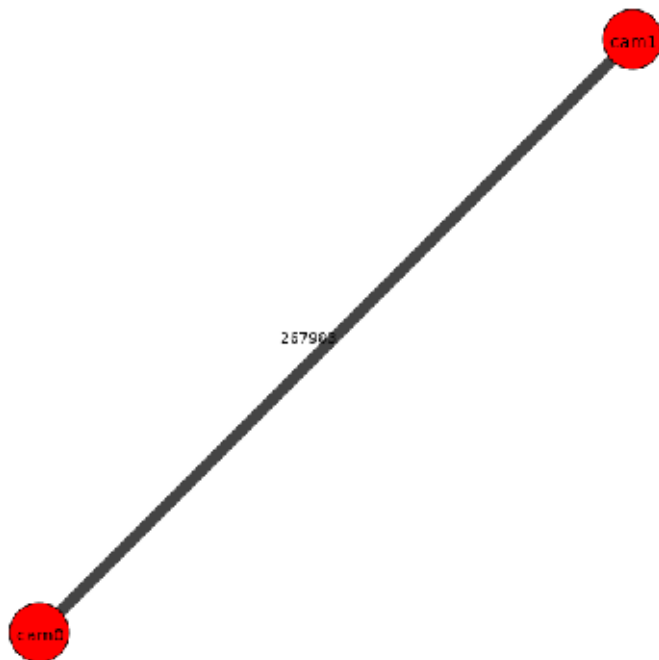
Rows: 6

Cols: 6

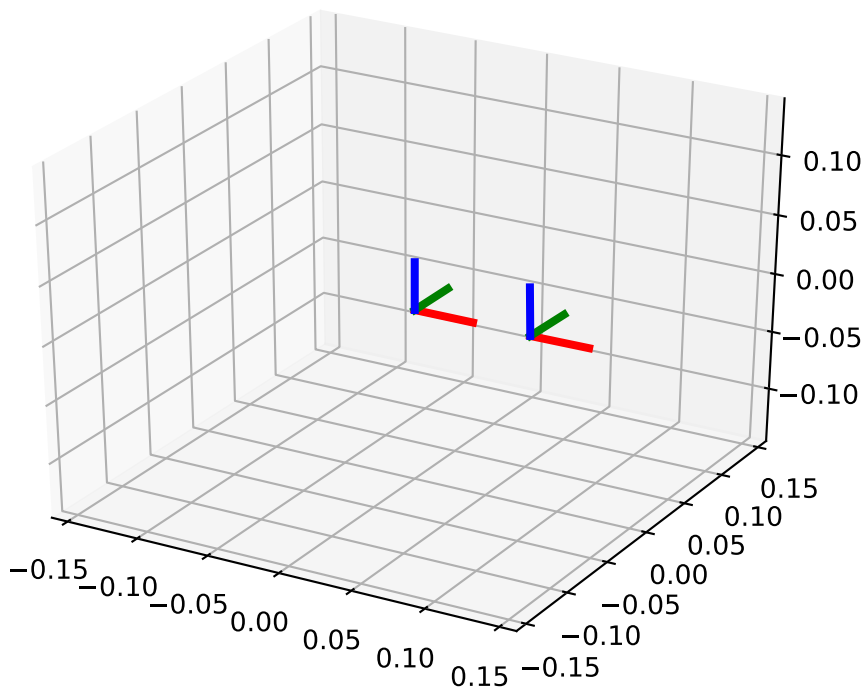
Size: 0.0312 [m]

Spacing 0.00959999976 [m]

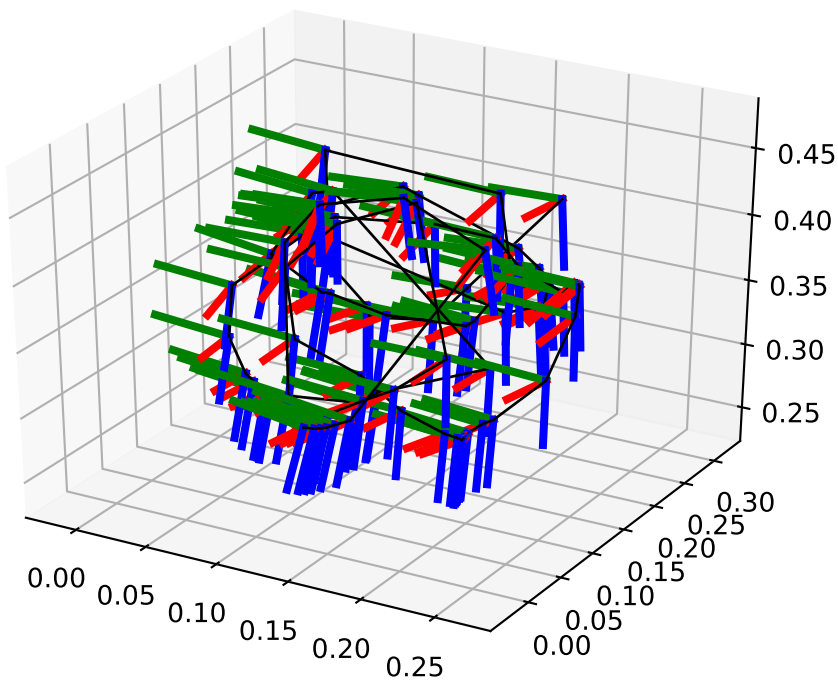
Inter-camera observations graph (edge weight=#mutual obs.)



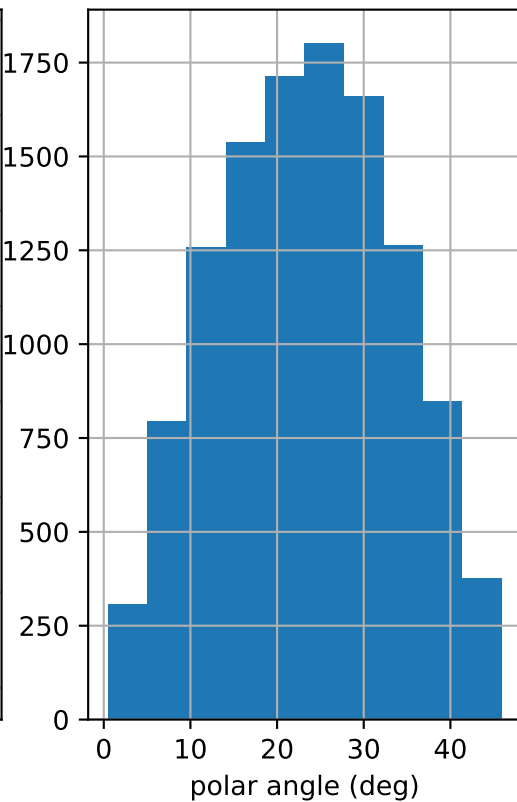
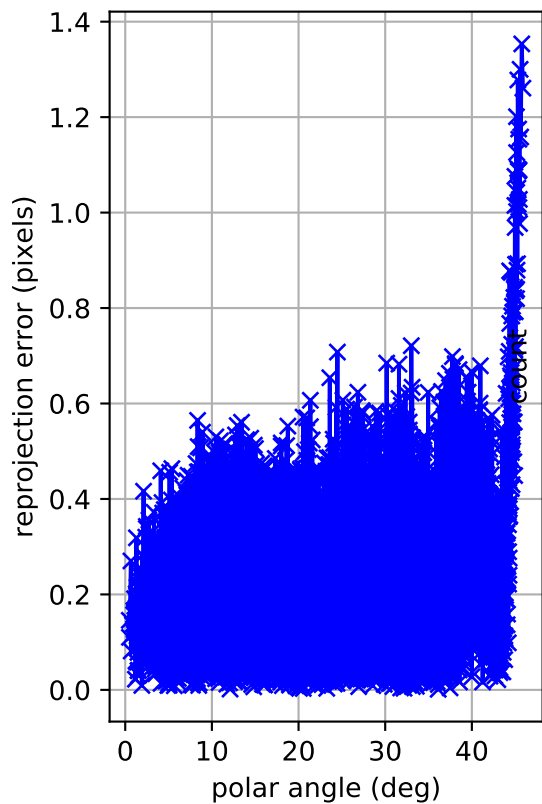
camera system



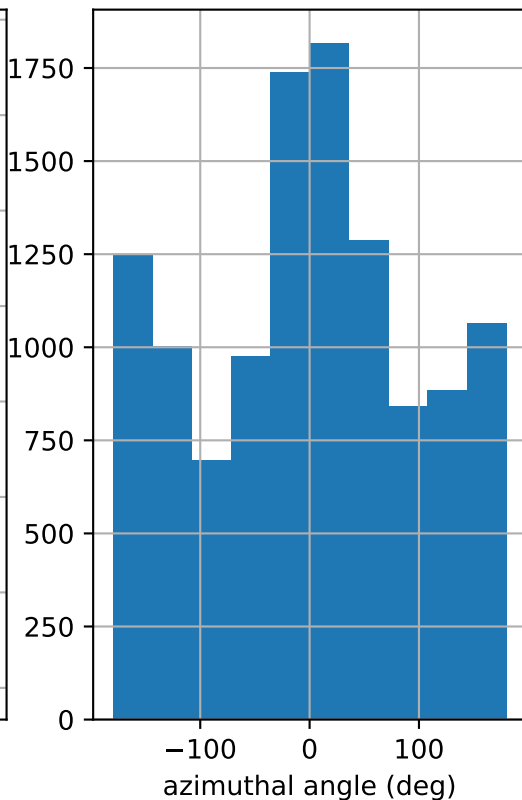
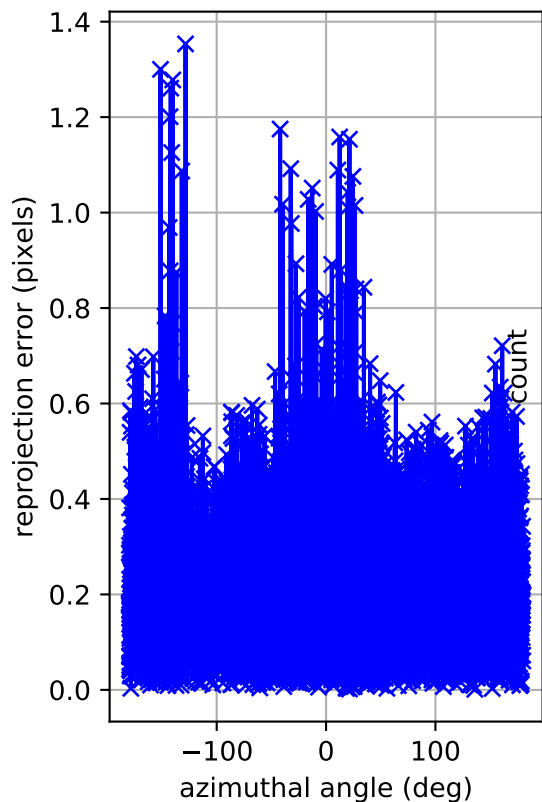
cam0: estimated poses



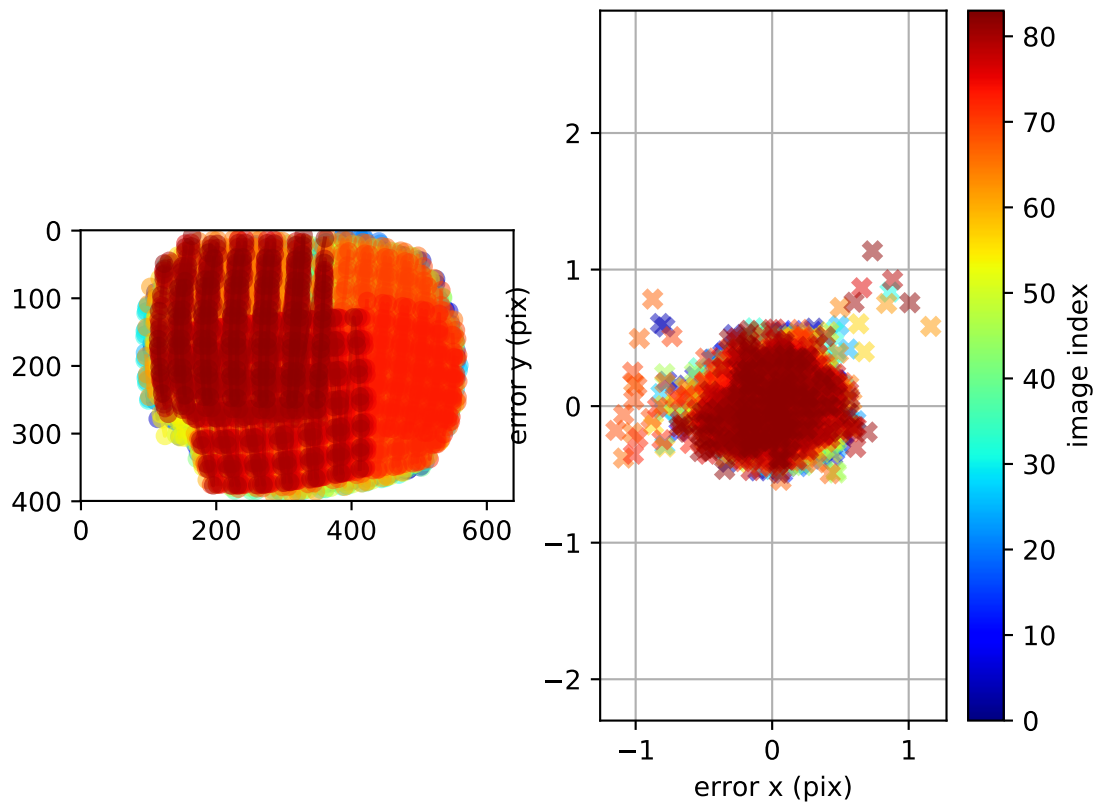
cam0: polar error



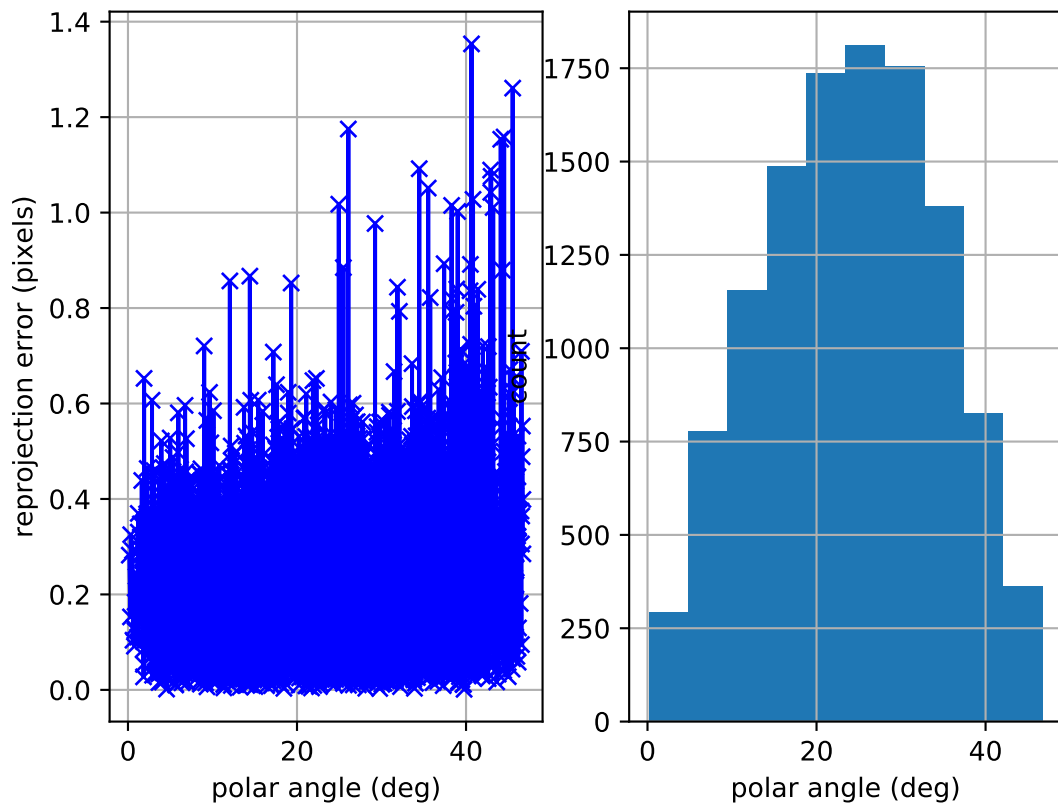
cam0: azimuthal error



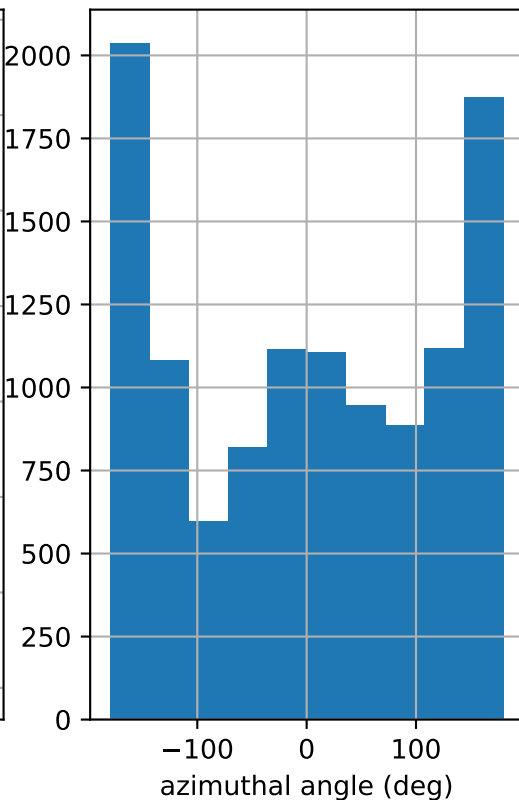
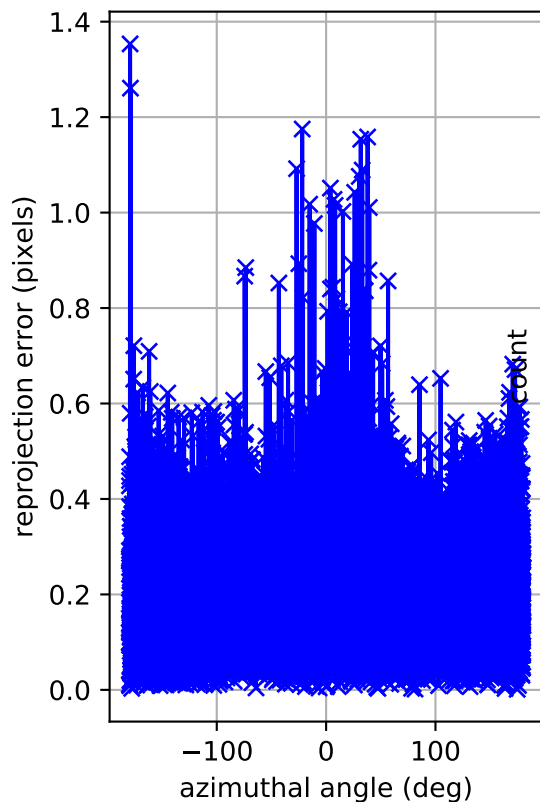
cam0: reprojection errors



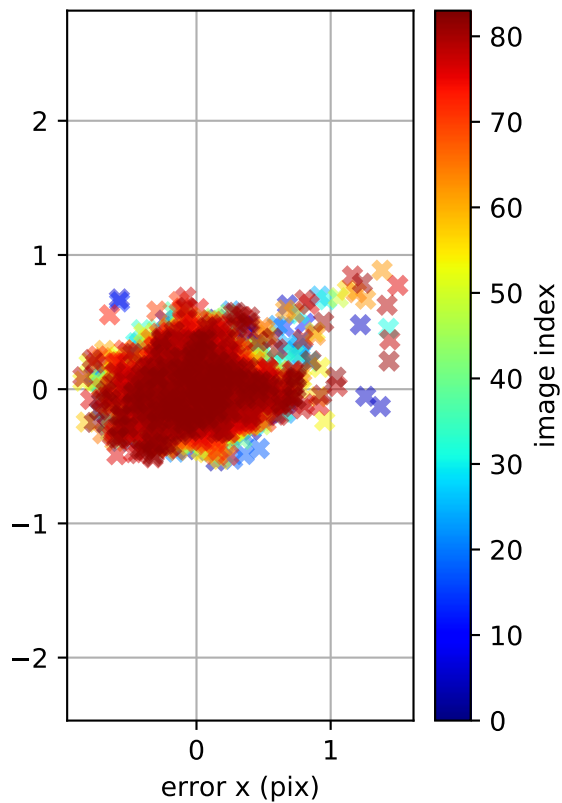
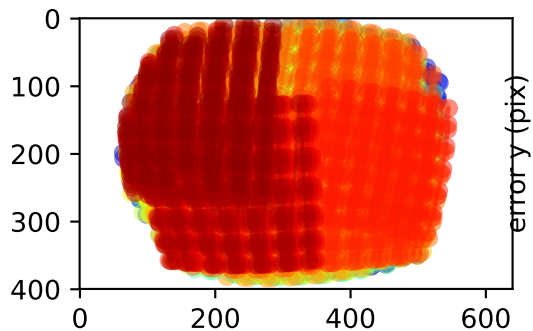
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

