

Calibration results

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Camera-system parameters:

cam0 (/cam0/image_raw):

type: <class 'aslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.3647465 0.17396834 -0.00291589 0.00101861] +- [0.00576874 0.00903464 0.00032912 0.0008776]

projection: [302.64959445 302.72567682 315.55733297 204.84798864] +- [0.12199361 0.12008147 0.54388008 0.61848961]

reprojection error: [-0.000005, -0.000016] +- [0.087948, 0.069754]

cam1 (/cam1/image_raw):

type: <class 'aslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.37000718 0.19706748 -0.00347257 0.00152763] +- [0.00686079 0.02200534 0.00037066 0.00052163]

projection: [302.57770677 302.58947817 314.12871518 205.24462898] +- [0.10935146 0.12231837 0.62941101 0.50039232]

reprojection error: [0.000000, -0.000021] +- [0.077278, 0.075115]

baseline T_1_0:

q: [-0.00384155 -0.00781128 -0.01224045 0.99988719] +- [0.00350396 0.0036993 0.00033216]

t: [-0.08053344 -0.00022971 0.00057876] +- [0.00037839 0.00036698 0.00035595]

Target configuration

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Type: aprilgrid

Tags:

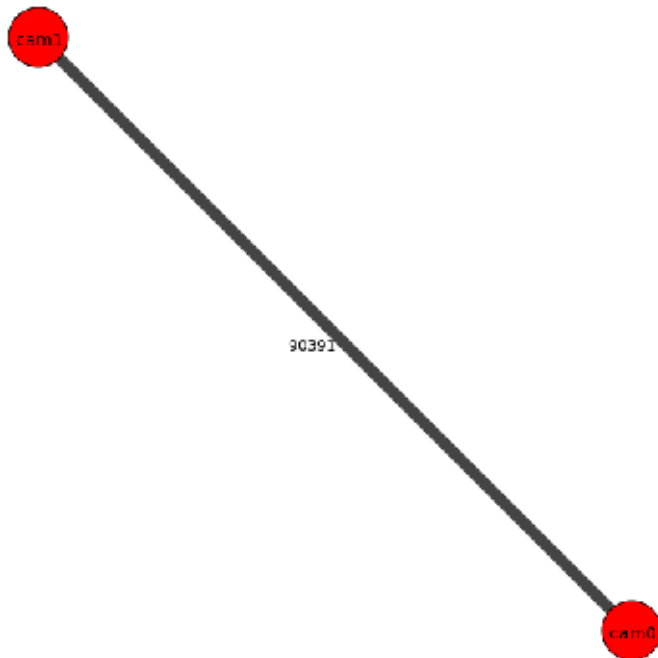
Rows: 6

Cols: 6

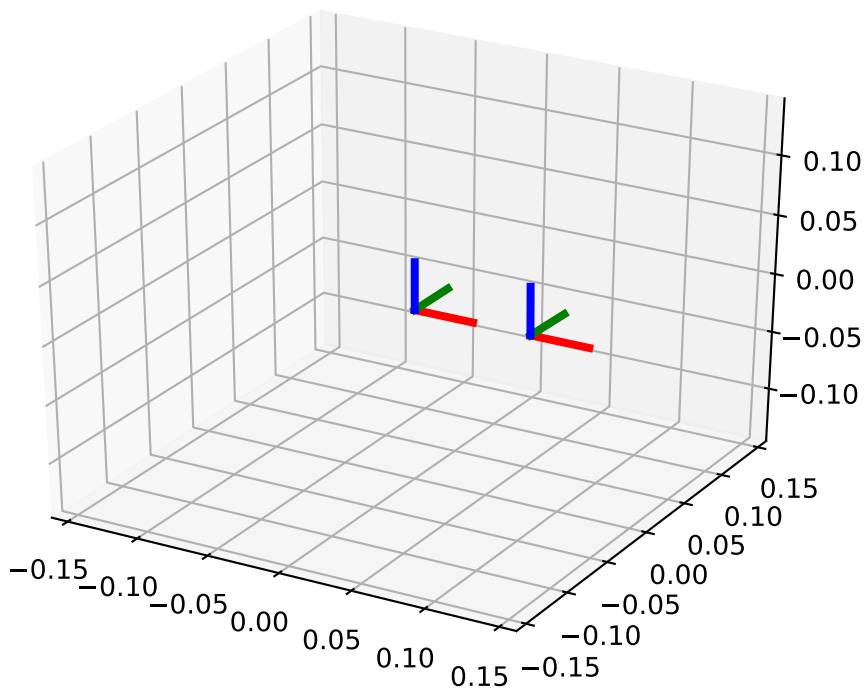
Size: 0.0312 [m]

Spacing 0.00959999976 [m]

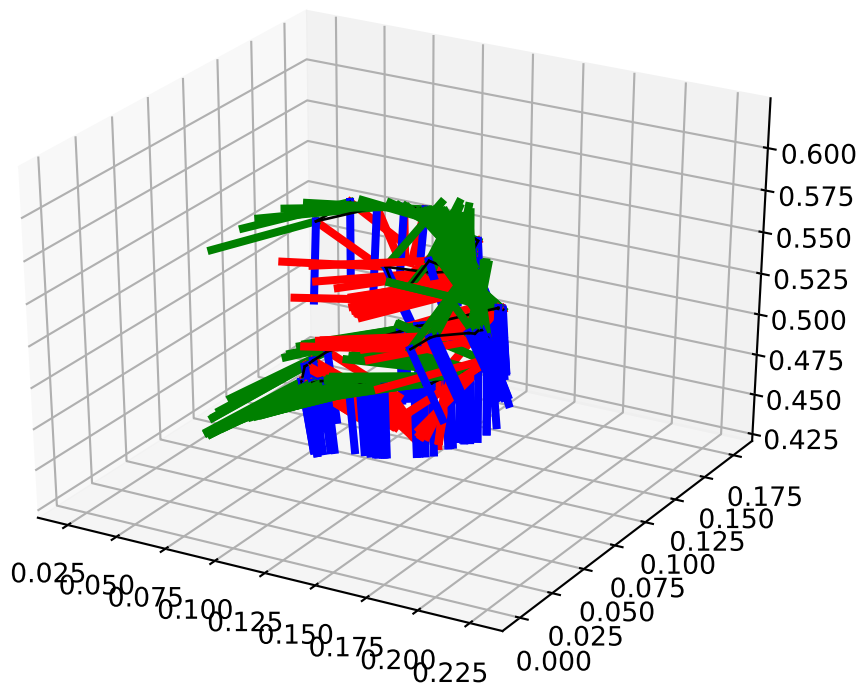
Inter-camera observations graph (edge weight=#mutual obs.)



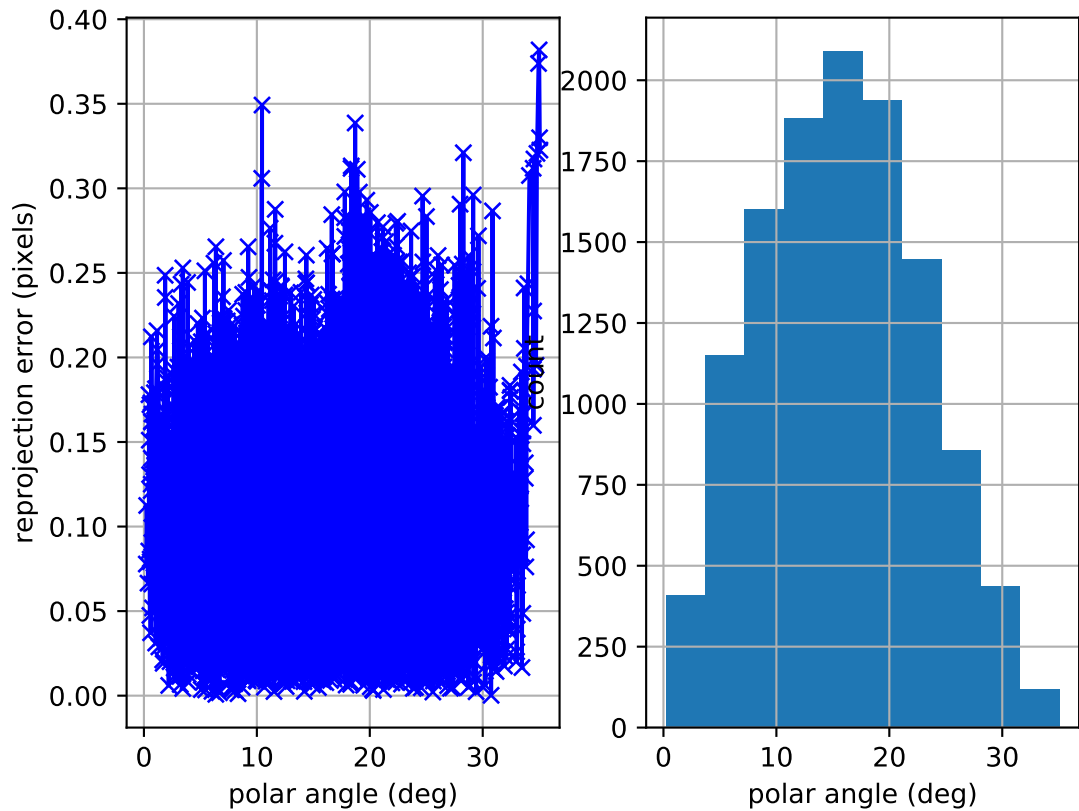
camera system



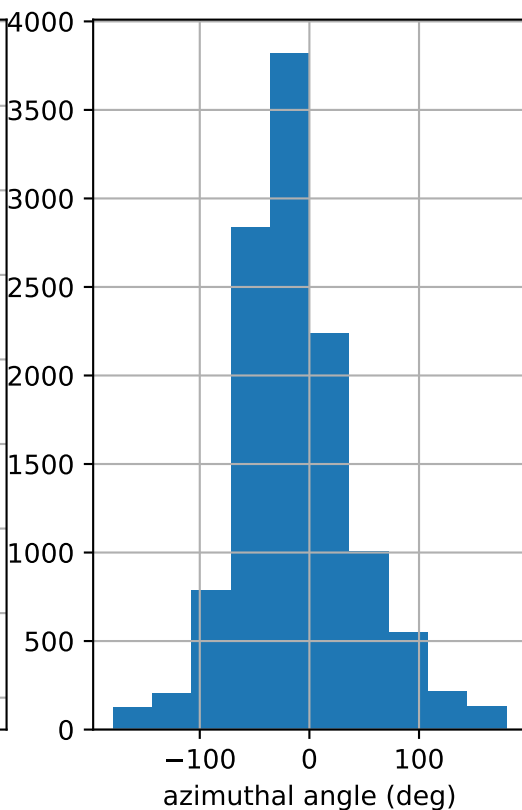
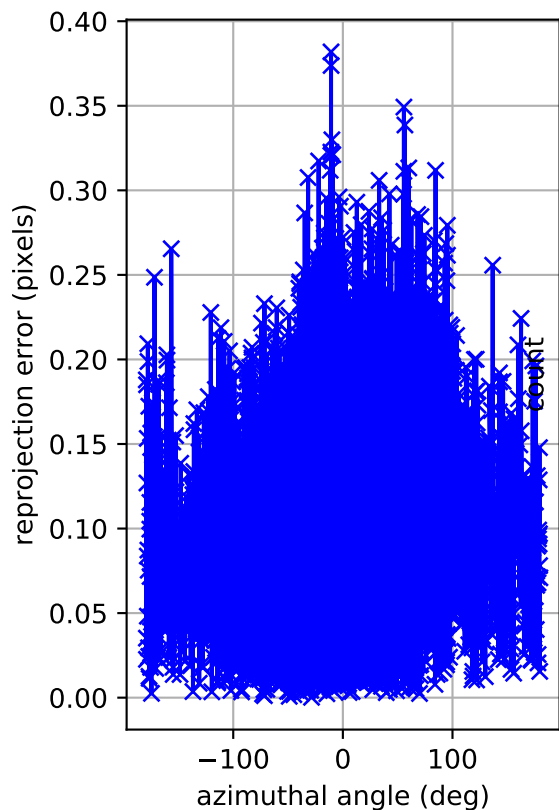
cam0: estimated poses



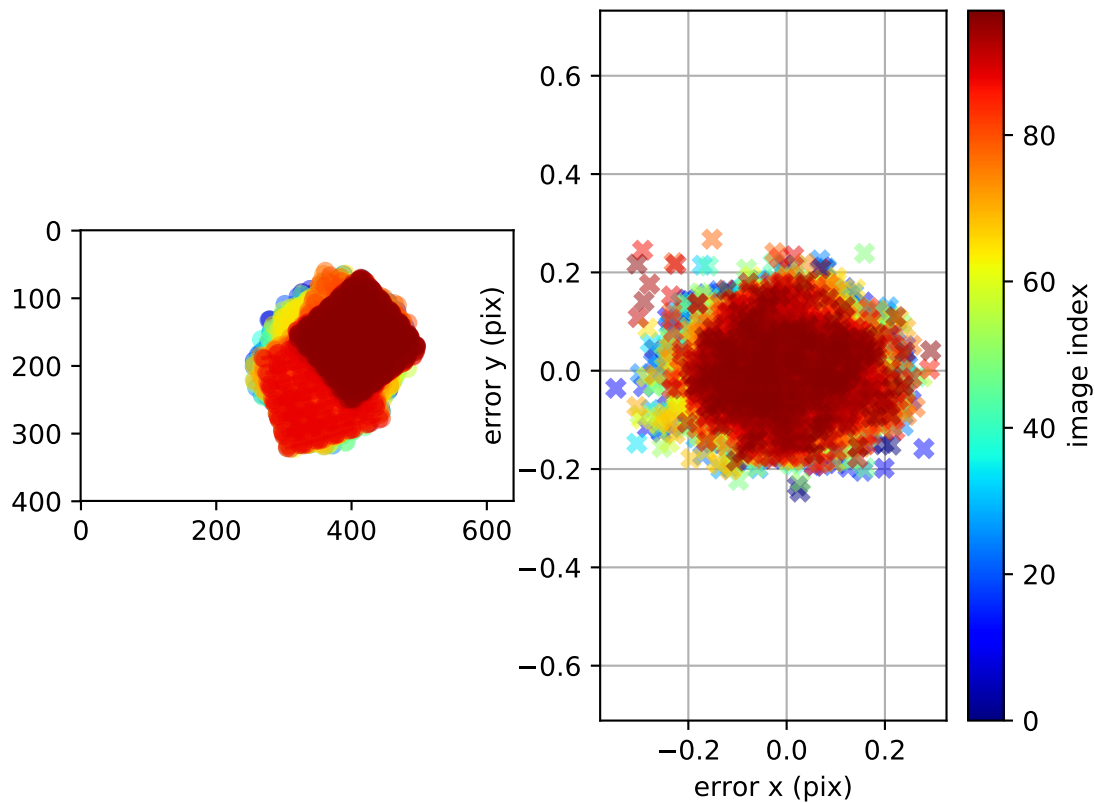
cam0: polar error



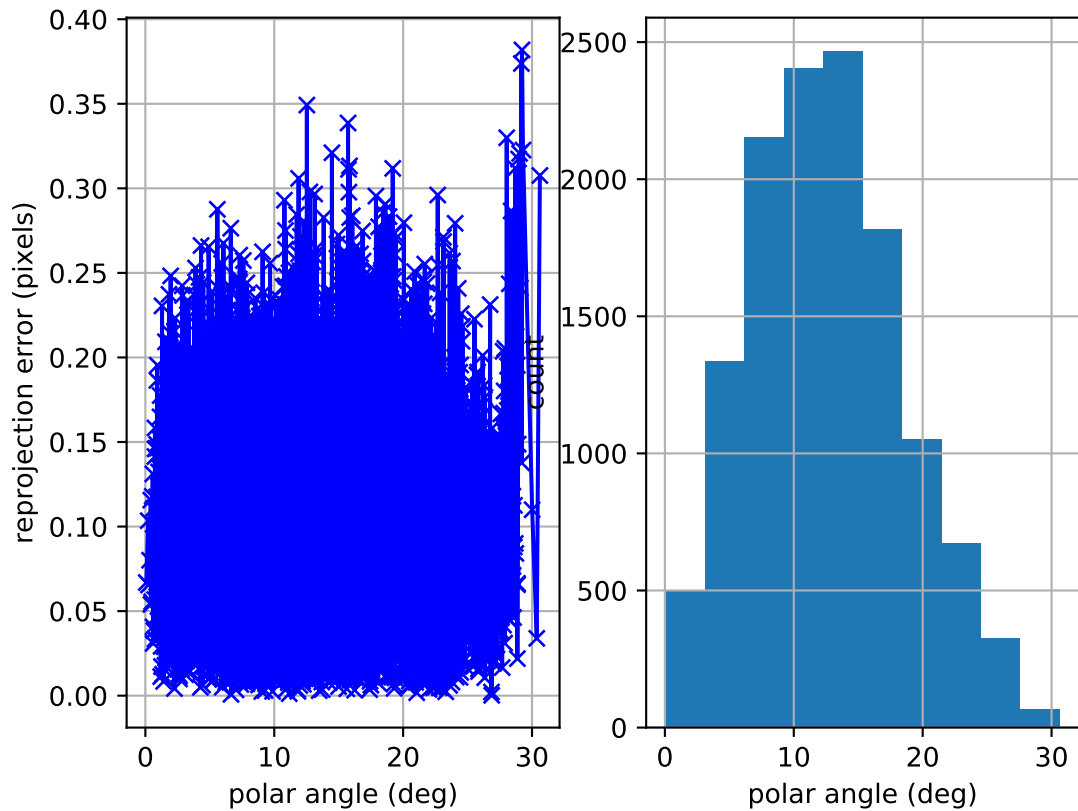
cam0: azimuthal error



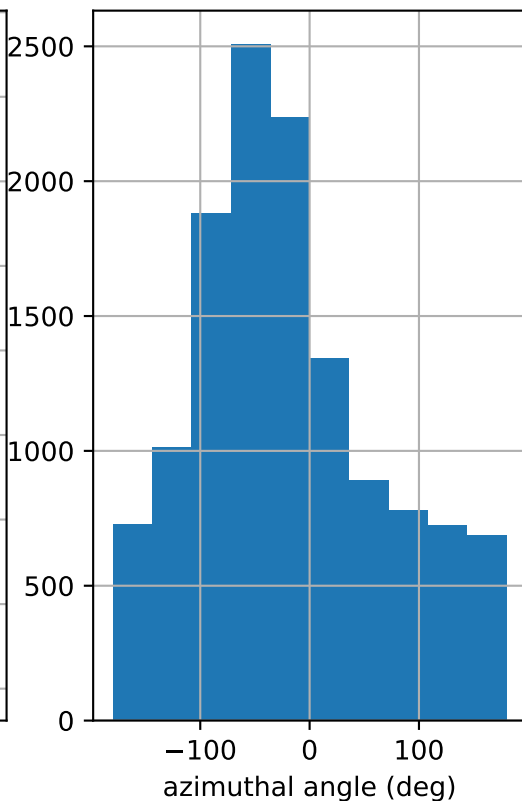
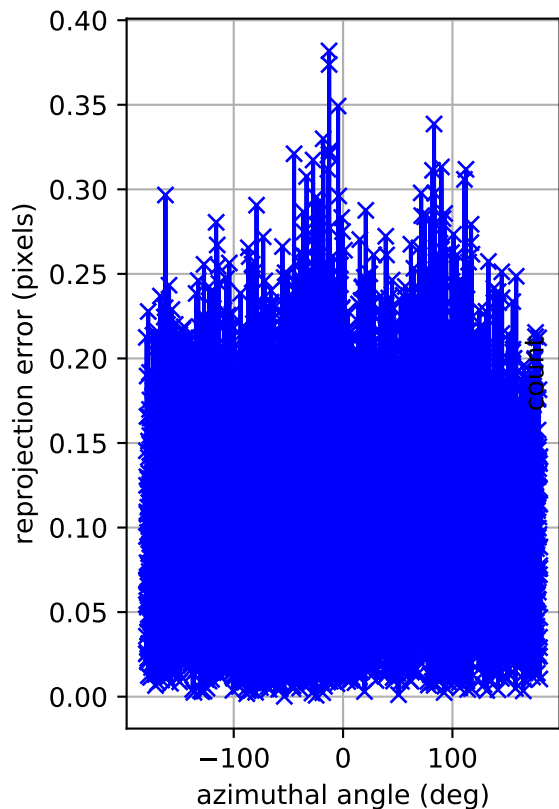
cam0: reprojection errors



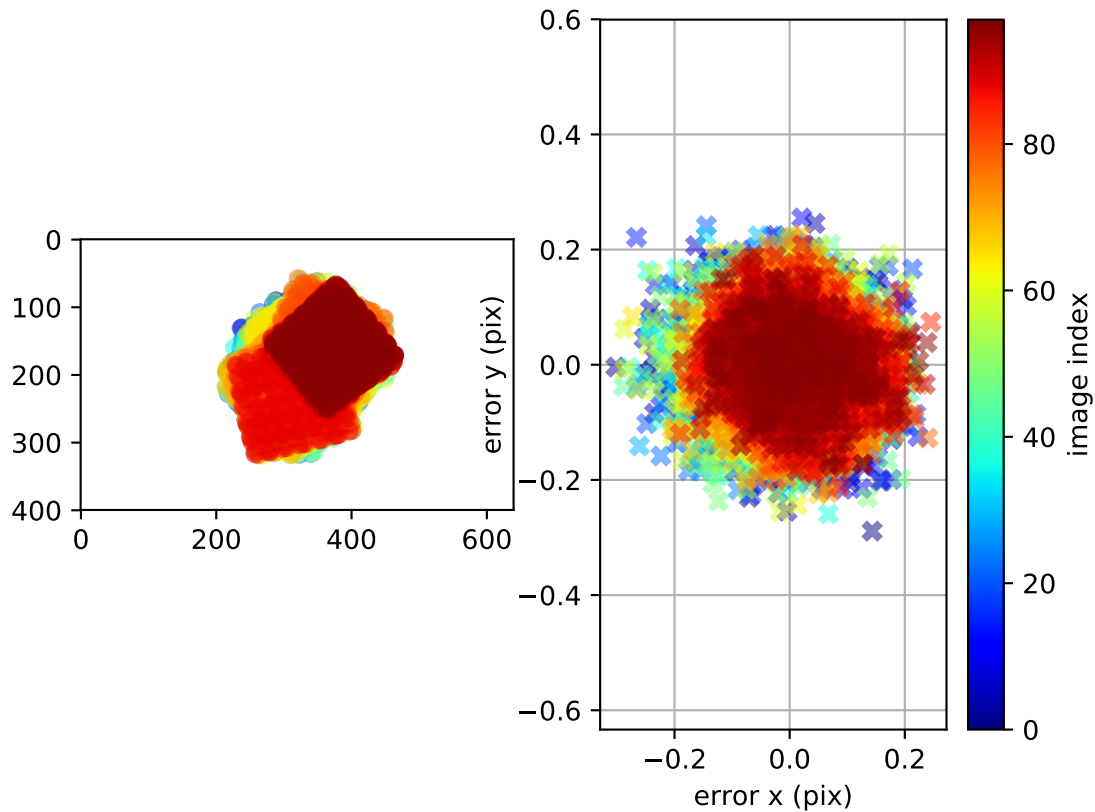
cam1: polar error



cam1: azimuthal error



cam1: reprojection errors



Location of removed outlier corners

