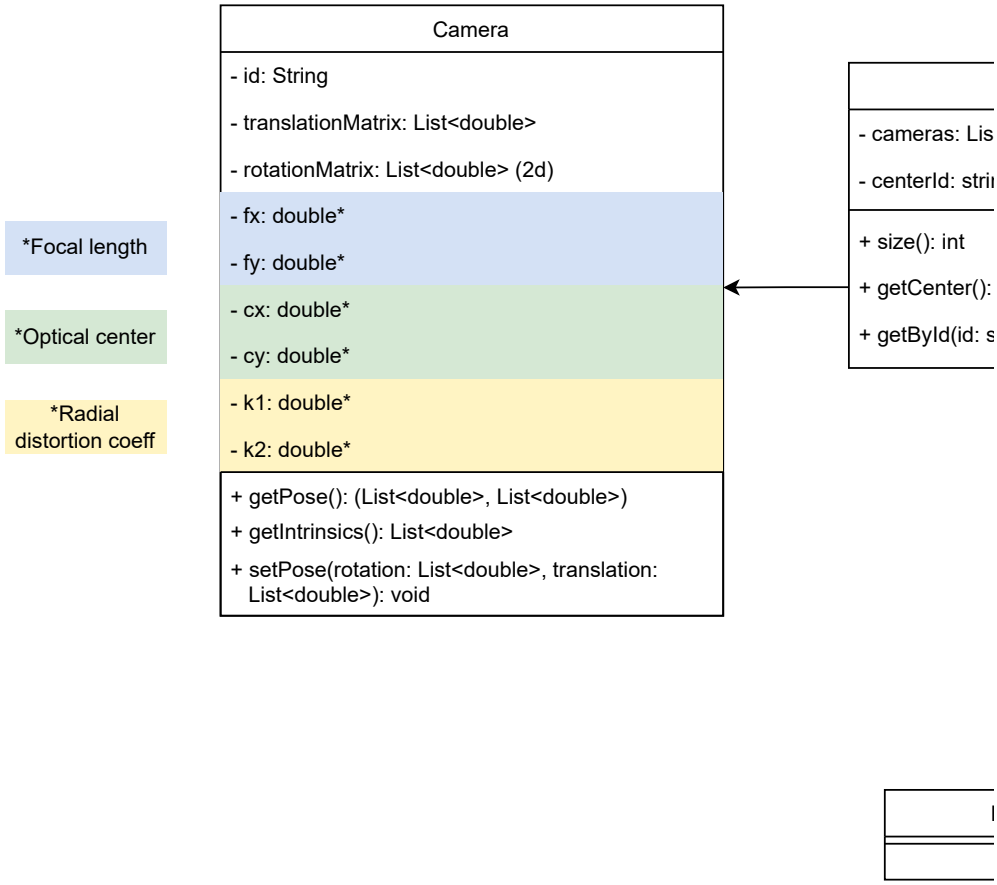
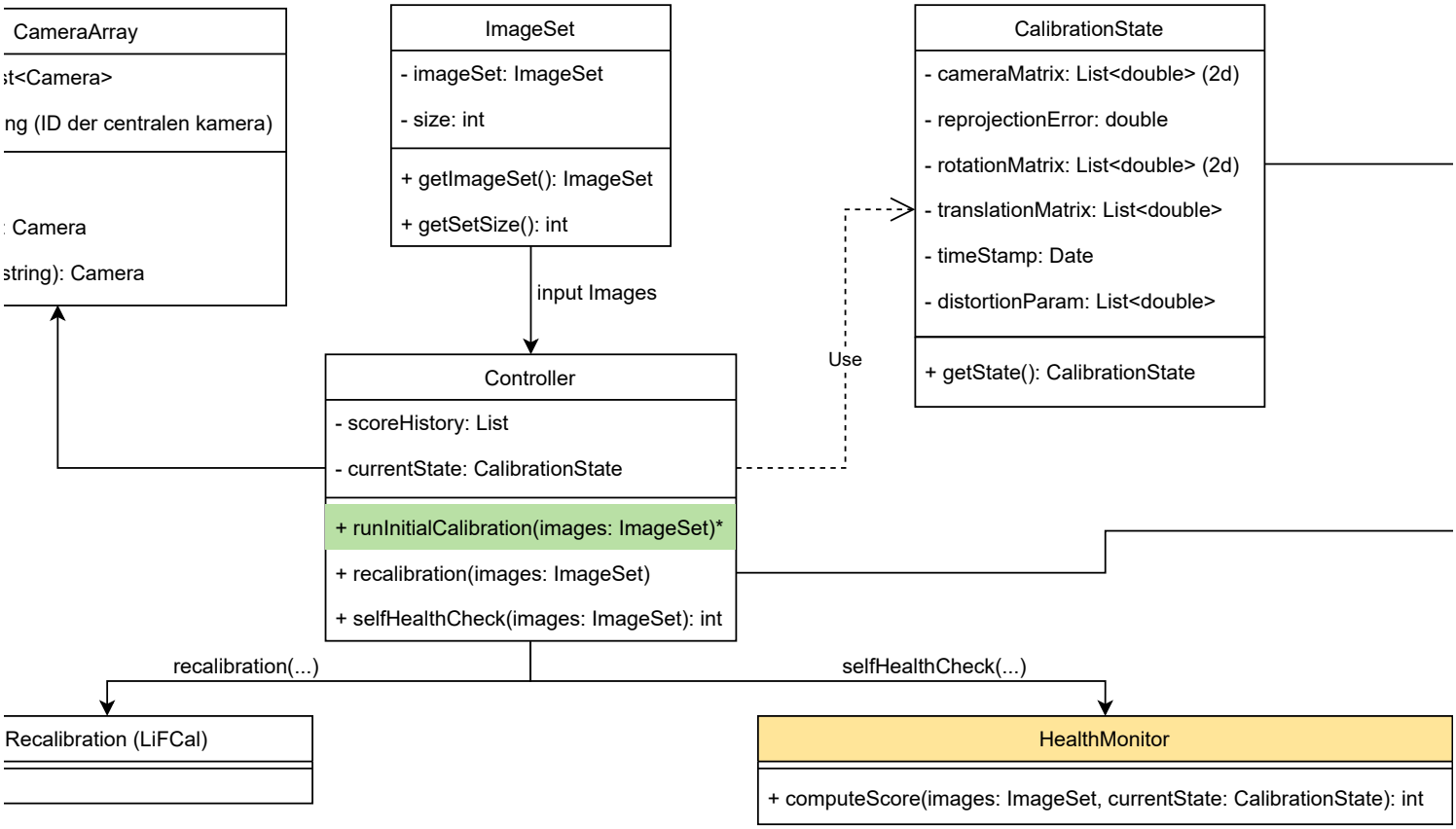
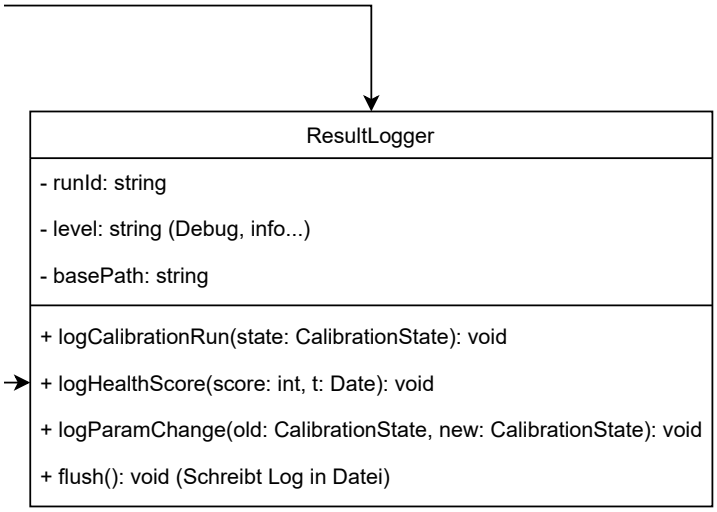

Camera
- id: String
- translationMatrix: List<double>
- rotationMatrix: List<double> (2d)
- fx: double*
- fy: double*
- cx: double*
- cy: double*
- k1: double*
- k2: double*
+ getPose(): (List<double>, List<double>)
+ getIntrinsics(): List<double>
+ setPose(rotation: List<double>, translation: List<double>): void
*Focal length
*Optical center
*Radial distortion coeff
- cameras: Lis
- centerId: stri
+ size(): int
+ getCenter():
+ getById(id: s



*Initalcalibration would be via OpenCV or LiFCal

*Healthscore is based on reprojectionerror, paremeter drift or a Feature-based check could be an option


ResultLogger
- runId: string
- level: string (Debug, info...)
- basePath: string
+ logCalibrationRun(state: CalibrationState): void
+ logHealthScore(score: int, t: Date): void
+ logParamChange(old: CalibrationState, new: CalibrationState): void
+ flush(): void (Schreibt Log in Datei)