Calibration results
====================
Camera-system parameters:
cam0 (/camera/camera/infra1/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.02852031 0.01438855 -0.00499885 0.00540381] +- [0.00270803 0.00356461 0.00057831 0.00064461]
projection: [405.30297741 404.54801996 331.75454887 234.66503989] +- [0.92675999 0.92103355 0.81276023 0.71643629]
reprojection error: [-0.000004, -0.000000] +- [0.360426, 0.323656]

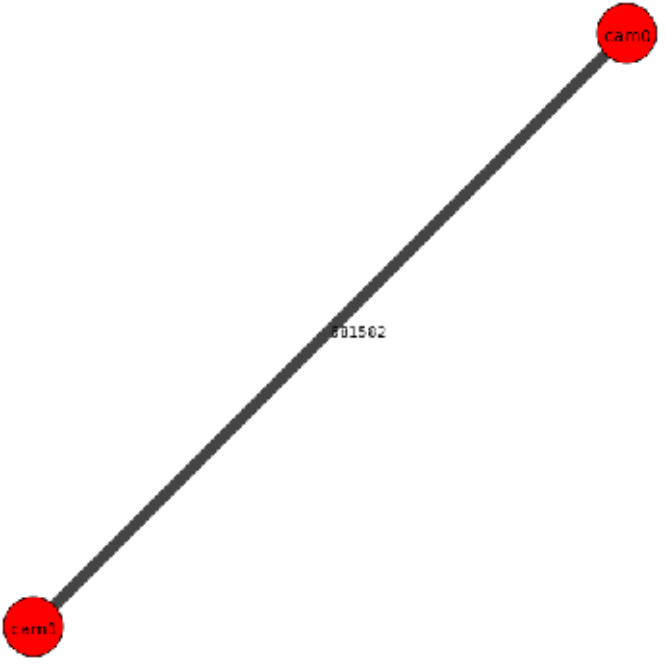
cam1 (/camera/camera/infra2/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.03756381 -0.00129735 -0.00539674 0.00168587] +- [0.00234526 0.00245732 0.00056245 0.00062086]
projection: [406.59876049 405.72068738 324.57883478 234.34477981] +- [0.91420476 0.90467905 0.76928029 0.71662678]
reprojection error: [0.000004, 0.000000] +- [0.303815, 0.324277]

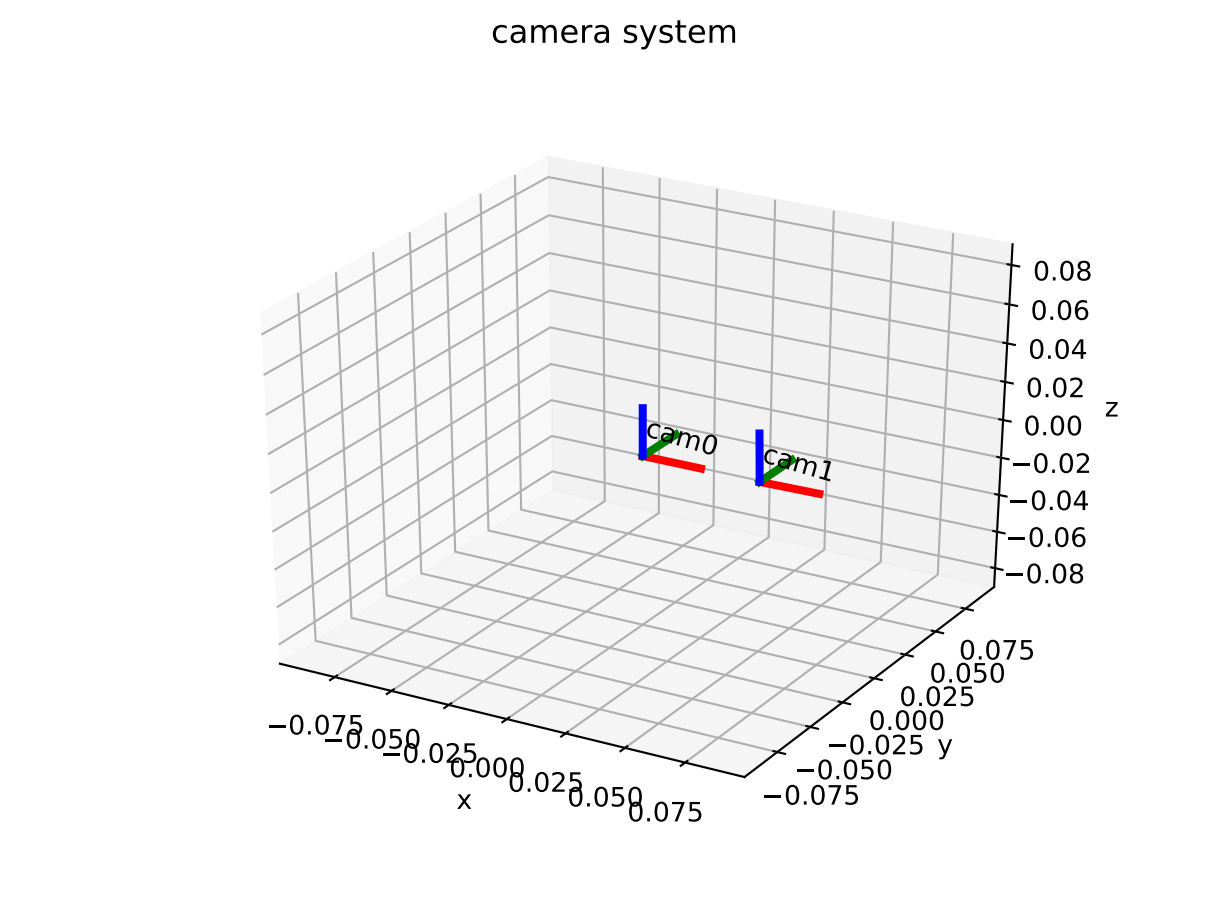
baseline T_1_0:
q: [-0.00049656 -0.00874215 0.00063965 0.99996146] +- [0.00114761 0.0016159 0.00017579]
t: [-0.04957204 0.00020893 0.00115061] +- [0.00009573 0.00009405 0.00030244]

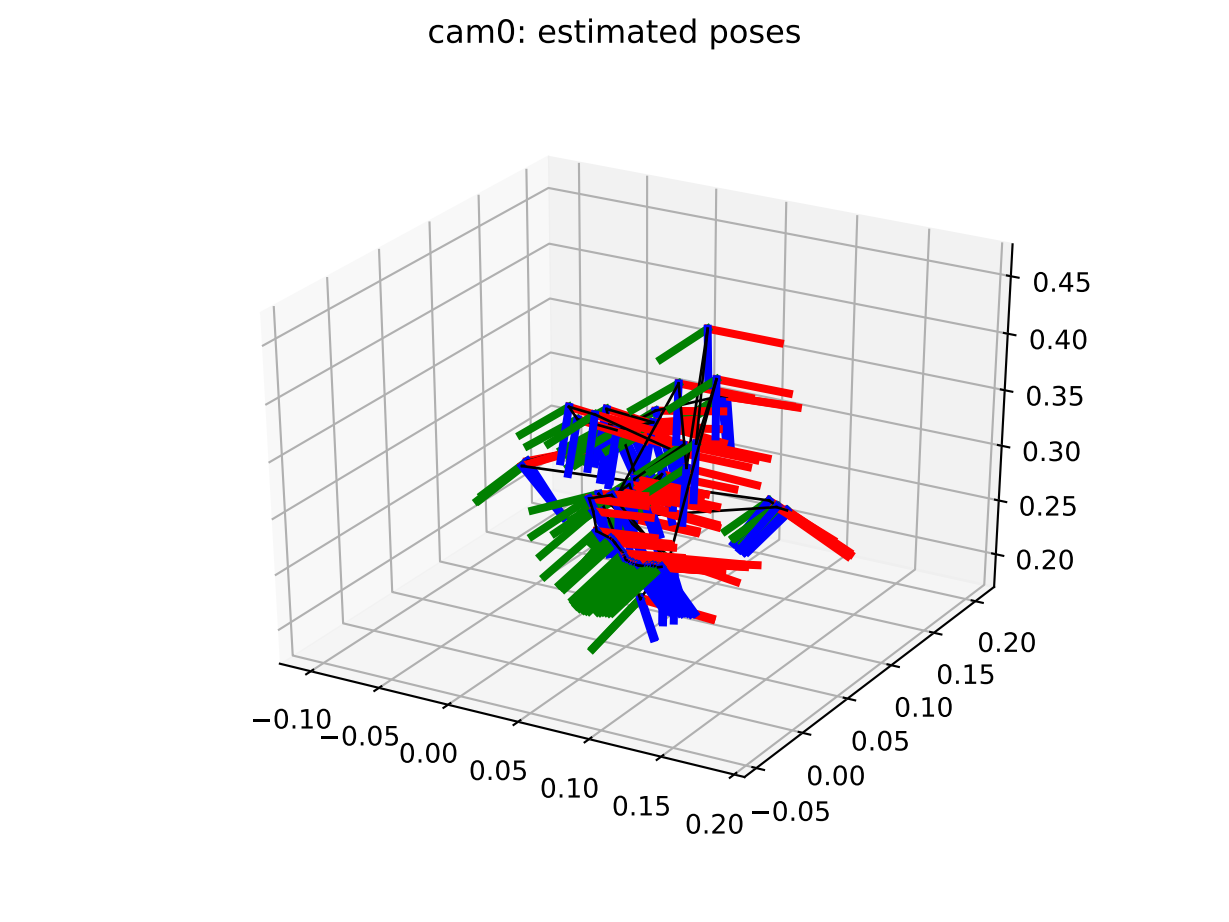
Target configuration
====================

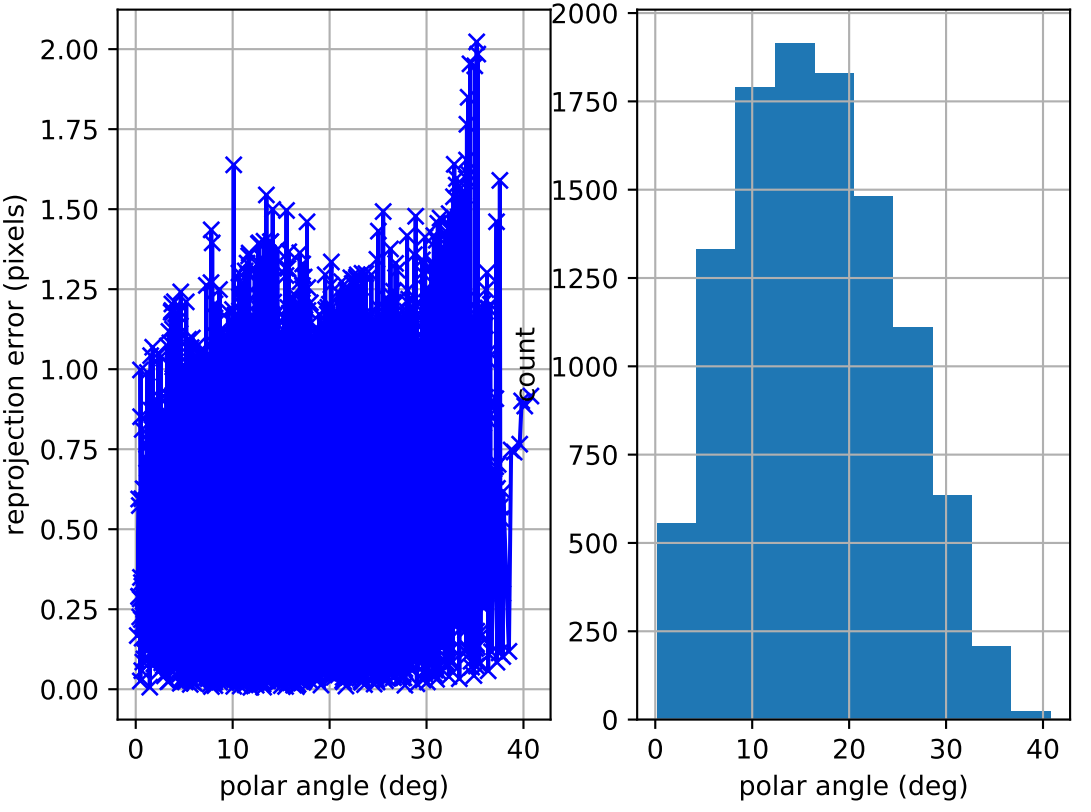
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0205 [m]
Spacing 0.00630006 [m]

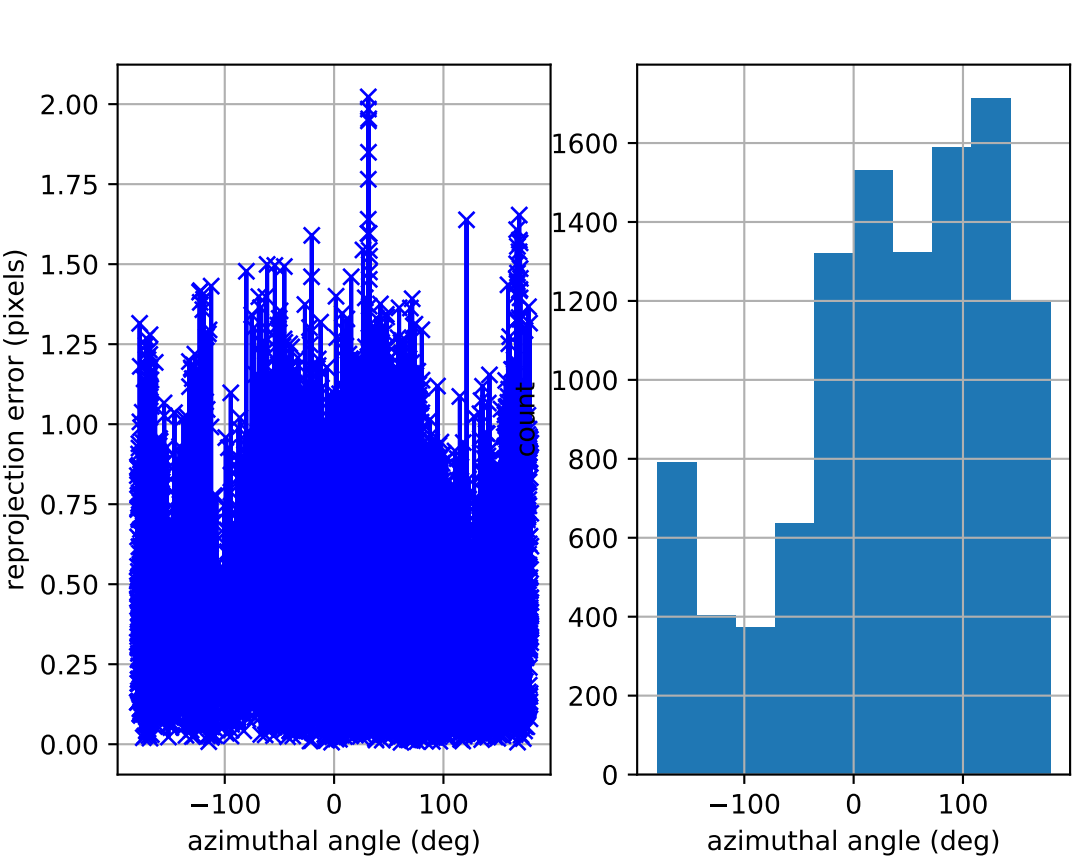
Inter-camera observations graph (edge weight=#mutual obs.)

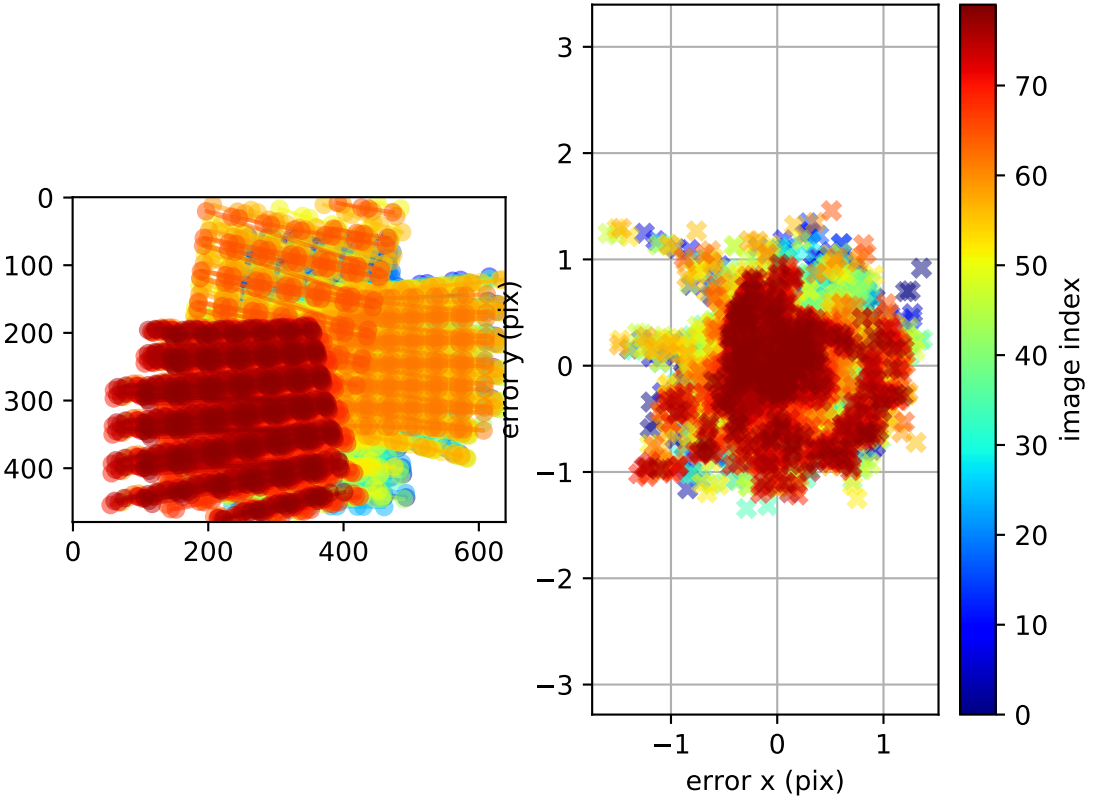


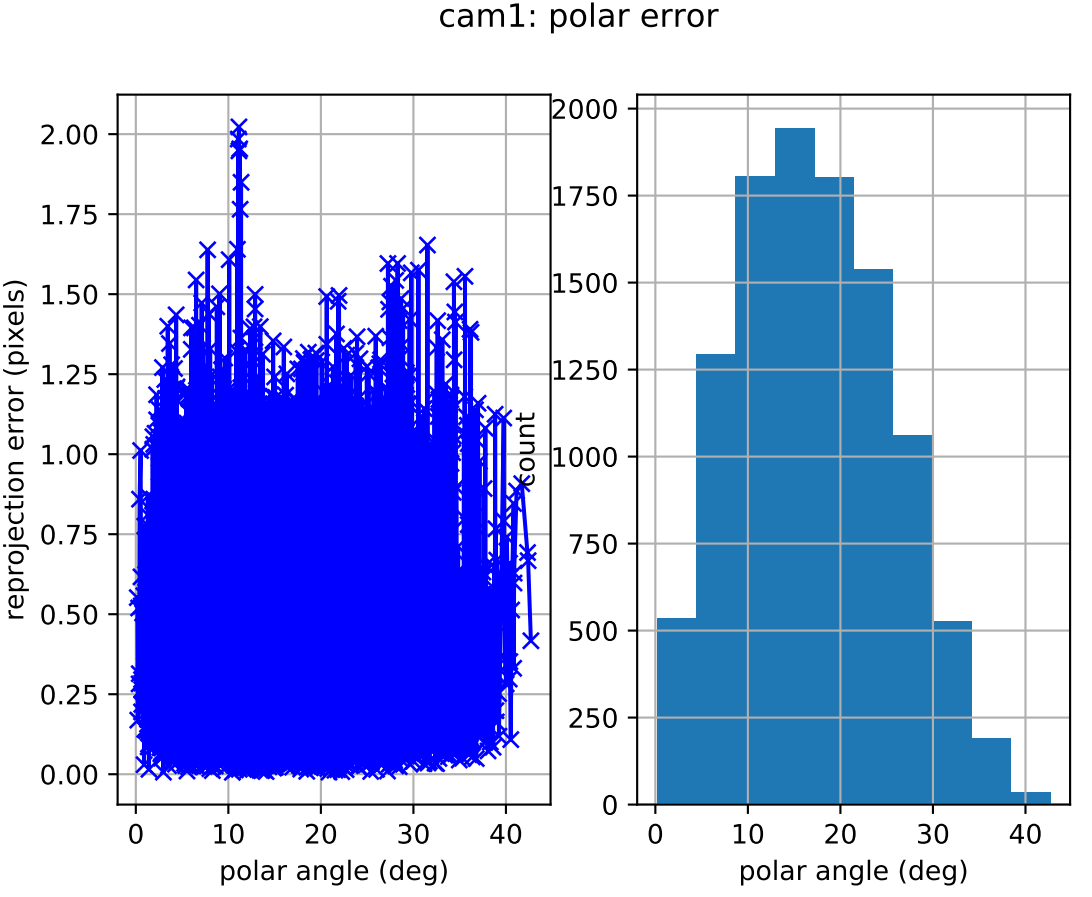

camera system
cam0
cam1
x
y
z
−0.075
−0.050
−0.025
0.000
0.025
0.050
0.075
0.08
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
−0.08

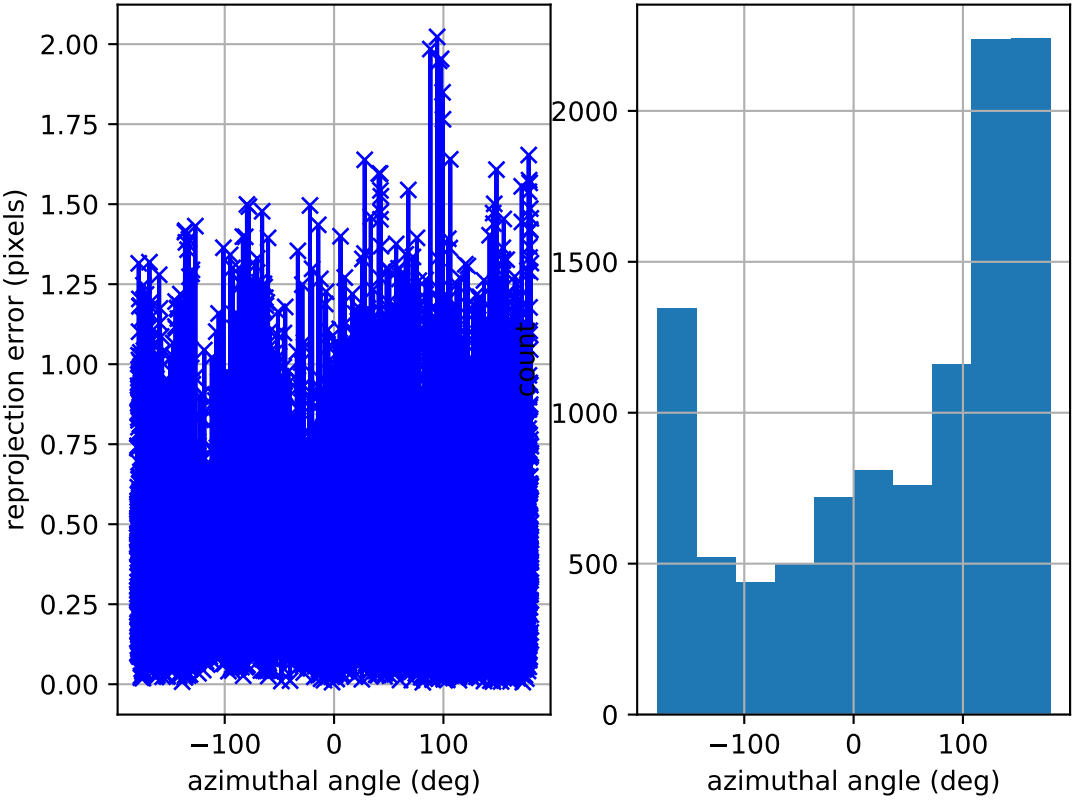

cam0: estimated poses
0.45
0.40
0.35
0.30
0.25
0.20
0.20
0.15
0.10
0.05
0.00
−0.05
−0.10
−0.05
0.00
0.05
0.10
0.15
0.20

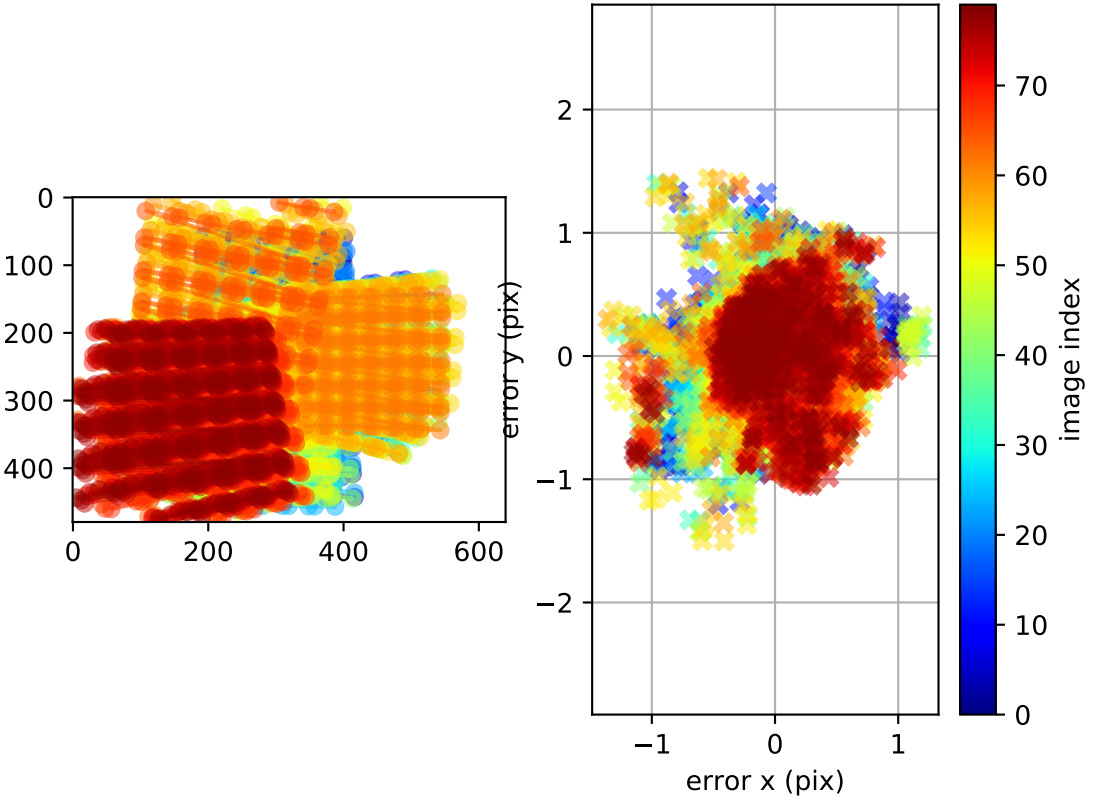

cam0: polar error
reprojection error (pixels)
2.00
1.75
1.50
1.25
1.00
0.75
0.50
0.25
0.00
0
10
20
30
40
polar angle (deg)
count
2000
1750
1500
1250
1000
750
500
250
0
0
10
20
30
40
polar angle (deg)

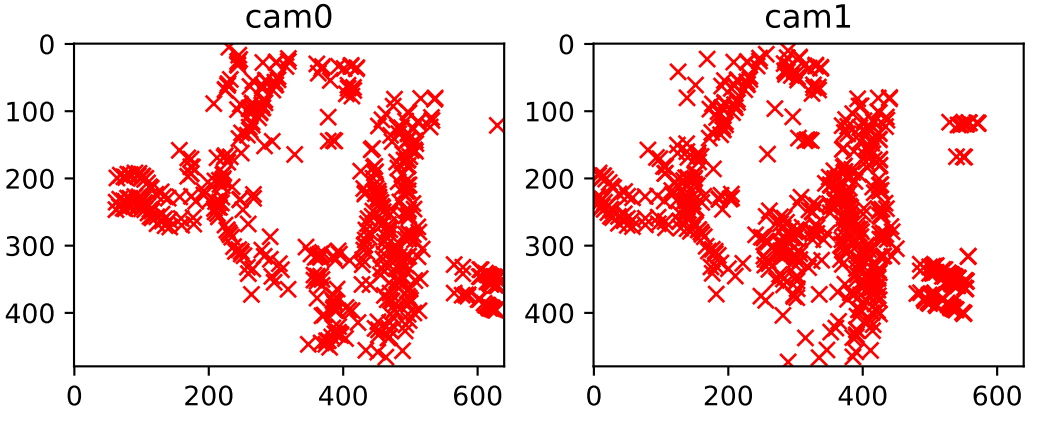

cam0: azimuthal error
reprojection error (pixels)
2.00
1.75
1.50
1.25
1.00
0.75
0.50
0.25
0.00
−100
0
100
azimuthal angle (deg)
count
1600
1400
1200
1000
800
600
400
200
0
−100
0
100
azimuthal angle (deg)


cam0: reprojection errors
0
100
200
300
400
0
200
400
600
error y (pix)
3
2
1
0
−1
−2
−3
−1
0
1
error x (pix)
70
60
50
40
30
20
10
0
image index


cam1: polar error
reprojection error (pixels)
2.00
1.75
1.50
1.25
1.00
0.75
0.50
0.25
0.00
0
10
20
30
40
polar angle (deg)
count
2000
1750
1500
1250
1000
750
500
250
0
0
10
20
30
40
polar angle (deg)


cam1: azimuthal error
reprojection error (pixels)
2.00
1.75
1.50
1.25
1.00
0.75
0.50
0.25
0.00
−100
0
100
azimuthal angle (deg)
count
2000
1500
1000
500
0
−100
0
100
azimuthal angle (deg)


cam1: reprojection errors
0
100
200
300
400
0
200
400
600
2
1
0
−1
−2
error y (pix)
−1
0
1
error x (pix)
70
60
50
40
30
20
10
0
image index


Location of removed outlier corners
cam0
cam1
0
100
200
300
400
0
200
400
600