Select poses to use for calibration ([]=all):

[2 3 4 5 6 7 9 11 12 19 20 21 22 23 24 25 27 28 29 30 31 32 33 34 35 36]

Initial calibration for camera 1:

Color internals:

Focal length: [1106.27 1091.68]

Principal point: [646.00 274.78]

Distortion: [-0.4645 2.3316 -0.0246 -0.0044 -3.2839]

Relative pose:

Rotation: [1.00000 0.00000 0.00000;

0.00000 1.00000 0.00000;

0.00000 0.00000 1.00000]

Translation: [0.00000 0.00000 0.00000]

Reprojection error std. dev.: 2.130197

Initial calibration for camera 2:

Color internals:

Focal length: [959.75 950.72]

Principal point: [322.10 139.54]

Distortion: [-0.4982 6.5917 -0.0026 0.0005 -24.3362]

Relative pose:

Rotation: [0.99926 -0.03549 -0.01498;

0.03759 0.98353 0.17681;

0.00846 -0.17724 0.98413]

Translation: [-0.00194 0.06826 0.06590]

Reprojection error std. dev.: 1.041557

Initial depth camera calibration

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Using well known values for initial depth camera calibration

Estimating initial pose for depth-only images...

Optimizing depth camera parameters...

Stats with initial values:

Color 1: mean=-0.043459, std=2.130197 [-0.052718,+0.055338] (pixels)

Color 2: mean=-0.017980, std=1.041557 [-0.025777,+0.027057] (pixels)

Depth : mean=1310.038302, std=543.879407 [-0.680830,+0.682465] (disparity)

Obtaining samples...done

Minimizing cost function over 14 parameters..........Done 0.96635s

Stats after depth params optimization:

Color 1: mean=-0.043459, std=2.130197 [-0.052718,+0.055338] (pixels)

Color 2: mean=-0.017980, std=1.041557 [-0.025777,+0.027057] (pixels)

Depth : mean=-107.439185, std=479.396793 [-0.600111,+0.601551] (disparity)

Depth internals:

Focal length: [590.00 590.00]

Principal point: [320.00 230.00]

Distortion: [0.0000 0.0000 0.0000 0.0000 0.0000]

Depth params: [3.11 -0.001029]

Depth distortion alpha: [0.0000 0.0000]

Relative pose:

Rotation: [1.00000 -0.00000 0.00001;

0.00000 1.00000 0.00005;

-0.00001 -0.00005 1.00000]

Translation: [-0.02500 0.00006 0.00003]