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

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

Initial calibration for camera 1:

Color internals:

Focal length: [1143.90 1128.30]

Principal point: [656.72 280.16]

Distortion: [-0.4332 2.5602 -0.0292 -0.0034 -3.9872]

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.: 1.813737

Initial calibration for camera 2:

Color internals:

Focal length: [999.09 984.71]

Principal point: [329.33 140.50]

Distortion: [-0.7344 9.9332 -0.0008 0.0001 -37.8454]

Relative pose:

Rotation: [0.99923 -0.03580 -0.01574;

0.03793 0.98518 0.16728;

0.00952 -0.16775 0.98578]

Translation: [-0.00402 0.06765 0.06870]

Reprojection error std. dev.: 1.496261

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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=-0.000853, std=1.813737 [-0.046674,+0.049091] (pixels)

Color 2: mean=-0.000544, std=1.496261 [-0.038505,+0.040498] (pixels)

Depth : mean=1274.170840, std=542.982247 [-0.703107,+0.704853] (disparity)

Obtaining samples...done

Minimizing cost function over 14 parameters..........Done 0.94171s

Stats after depth params optimization:

Color 1: mean=-0.000853, std=1.813737 [-0.046674,+0.049091] (pixels)

Color 2: mean=-0.000544, std=1.496261 [-0.038505,+0.040498] (pixels)

Depth : mean=-139.046371, std=478.963856 [-0.620210,+0.621750] (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 -0.001033]

Depth distortion alpha: [0.0000 0.0000]

Relative pose:

Rotation: [1.00000 -0.00000 -0.00000;

0.00000 1.00000 0.00005;

0.00000 -0.00005 1.00000]

Translation: [-0.02501 0.00006 0.00004]