Calibration results
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Camera-system parameters:
cam0 (/zed/zed_node/left/gray/raw/image):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [0.04546553   3.6459603 -15.18538109 19.39493005] +- [0.01102195 0.11022568 0.44383405 0.60852942]
projection: [706.40059028 706.51498842 528.50424917 287.87360749] +- [0.51954876 0.52590195 0.50481372 0.5677183]
reprojection error: [-0.000141, 0.000127] +- [4.034197, 4.095317]

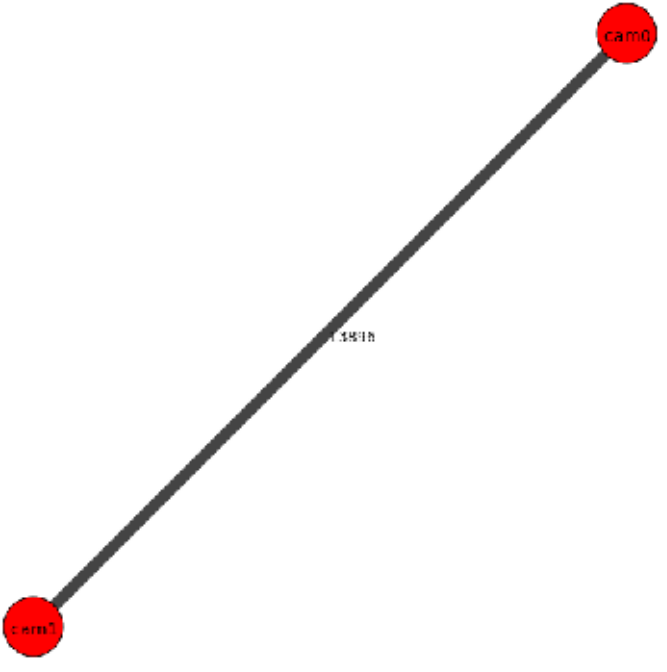
cam1 (/zed/zed_node/right/gray/raw/image):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [0.3781654   0.11809058 -0.84983841 0.39969724] +- [0.01042097 0.10413769 0.40207093 0.51532792]
projection: [696.08768196 696.55044018 465.37006356 300.9293951] +- [0.53589243 0.53720685 0.38893153 0.55857853]
reprojection error: [-0.000095, 0.000155] +- [4.159358, 4.079438]

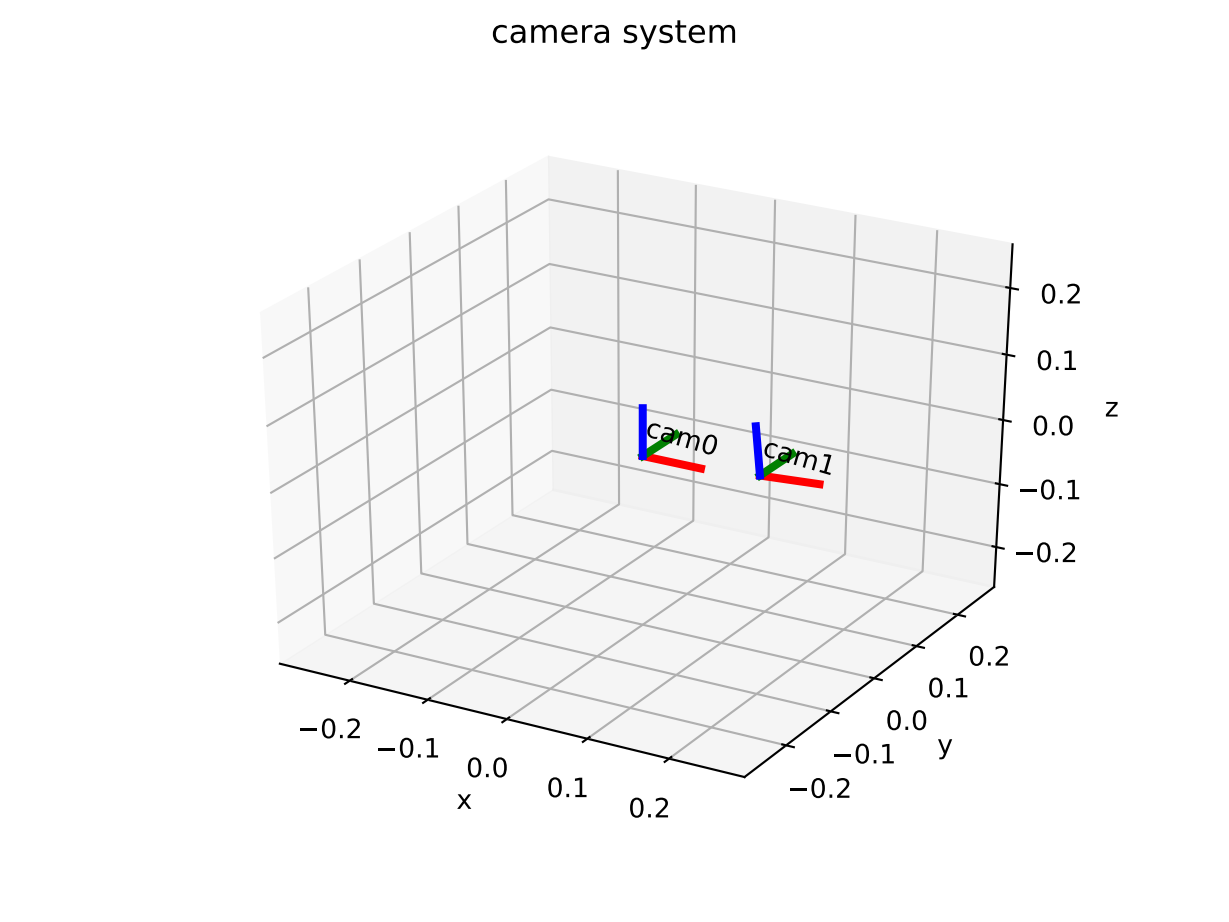
baseline T_1_0:
q: [-0.00216847 -0.04232554 0.00043899 0.99910142] +- [0.00049748 0.00069777 0.00011494]
t: [-0.14501362 -0.00024905 0.00391694] +- [0.00014441 0.00011598 0.0004821]

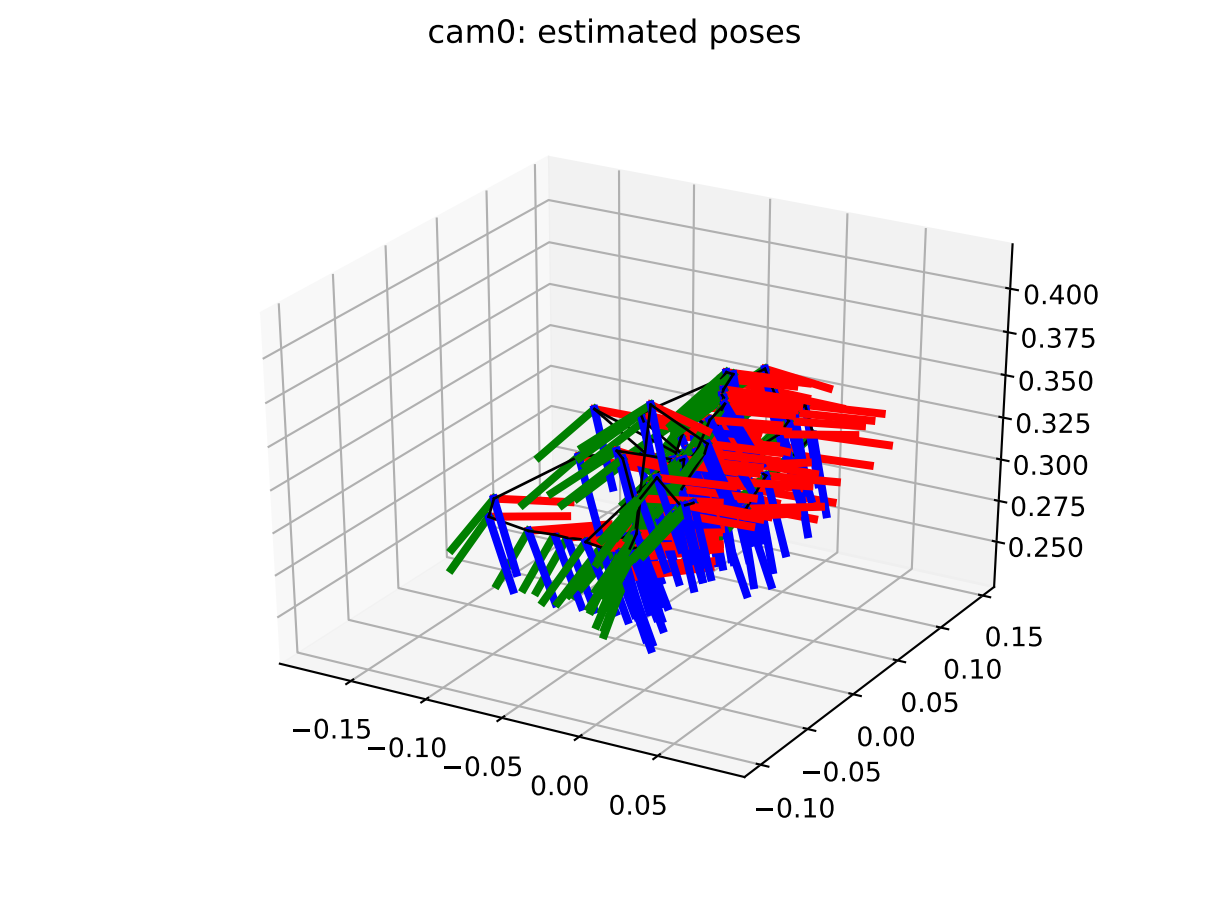
Target configuration
====================

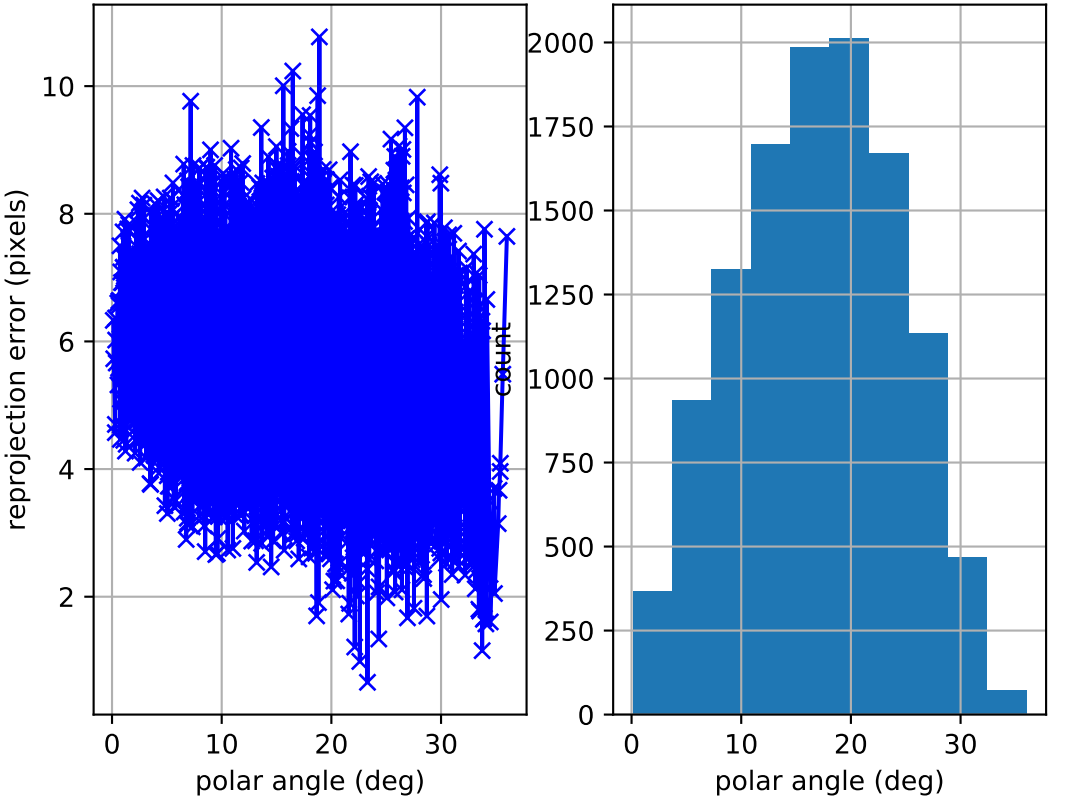
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.022 [m]
Spacing 0.0119999999999 [m]

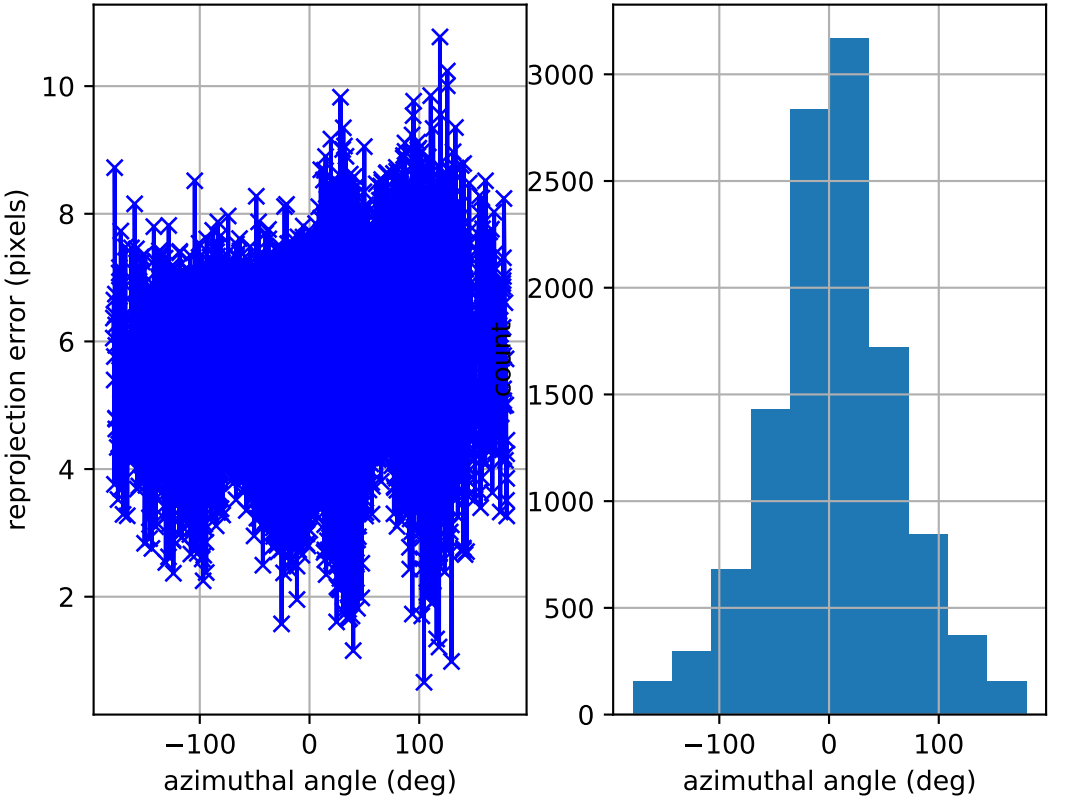
Inter-camera observations graph (edge weight=#mutual obs.)

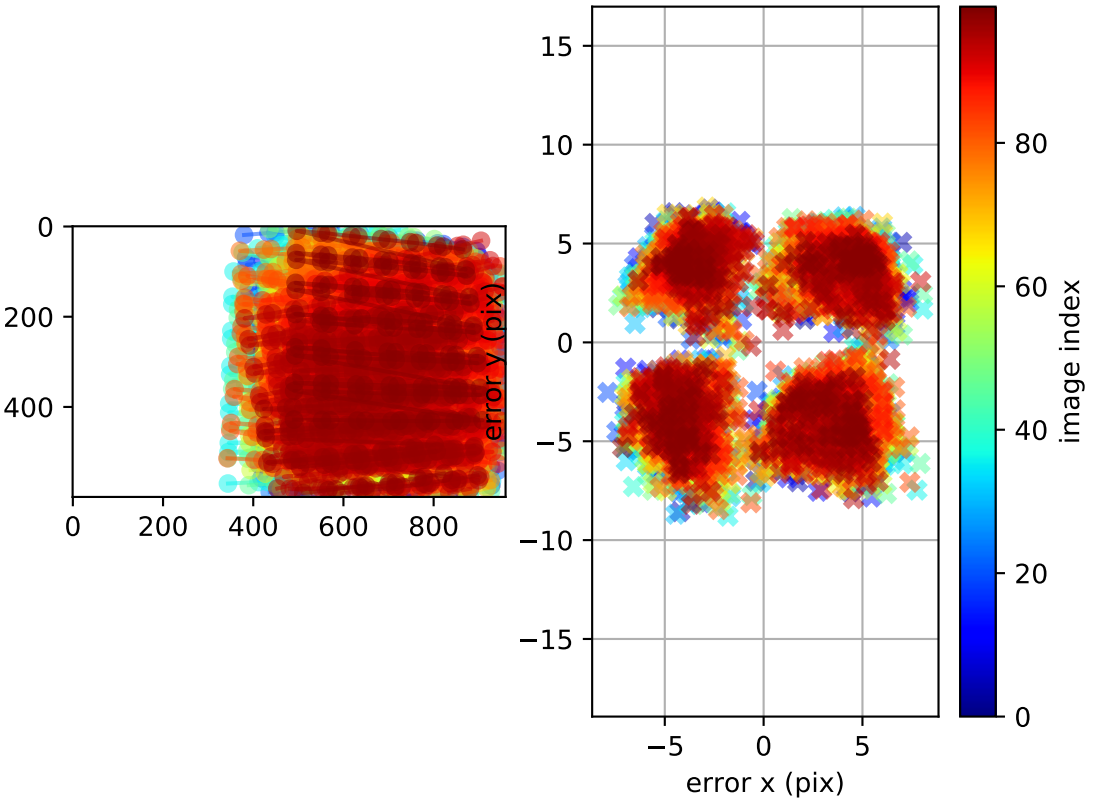


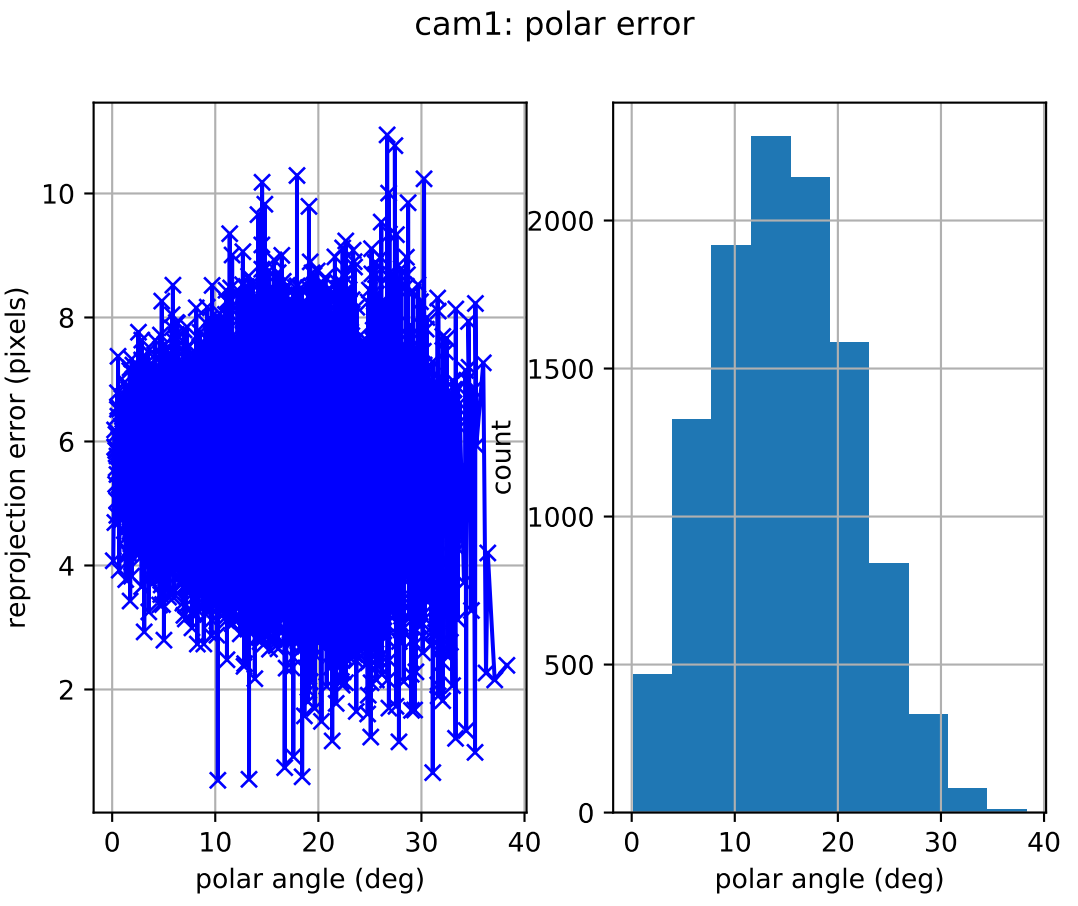

camera system
cam0
cam1
x
y
z
−0.2
−0.1
0.0
0.1
0.2

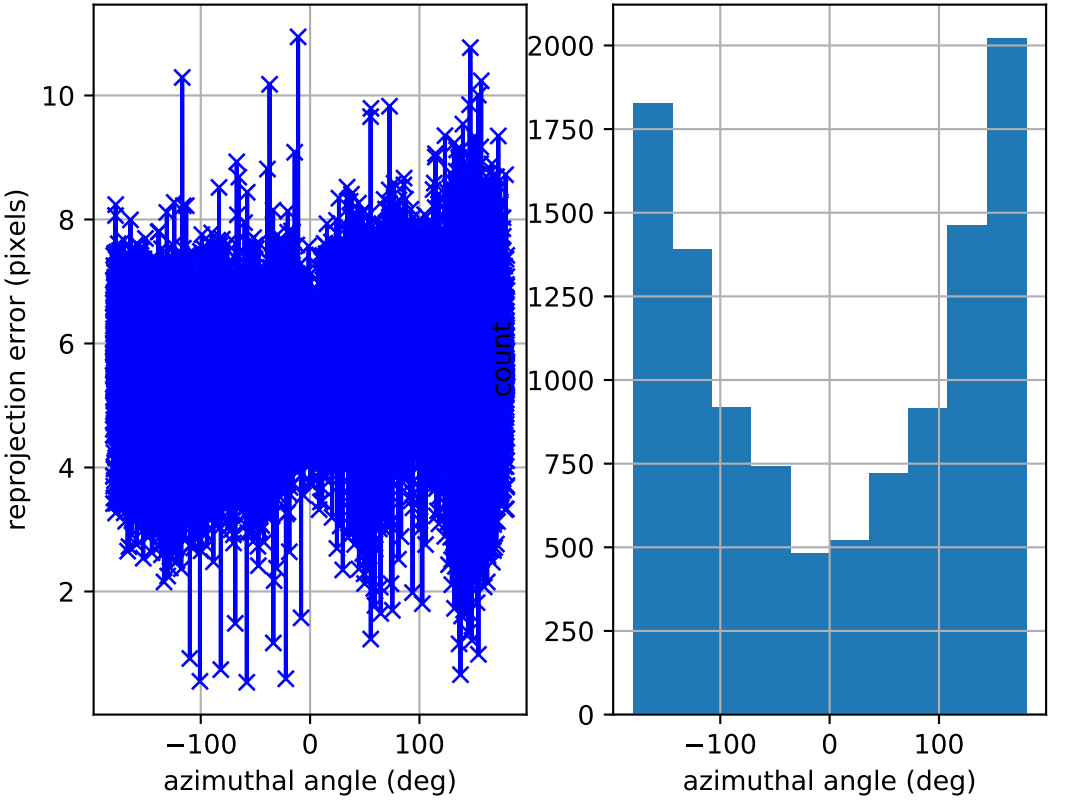

cam0: estimated poses
0.400
0.375
0.350
0.325
0.300
0.275
0.250
0.15
0.10
0.05
0.00
−0.05
−0.10
−0.15
−0.10
−0.05
0.00
0.05

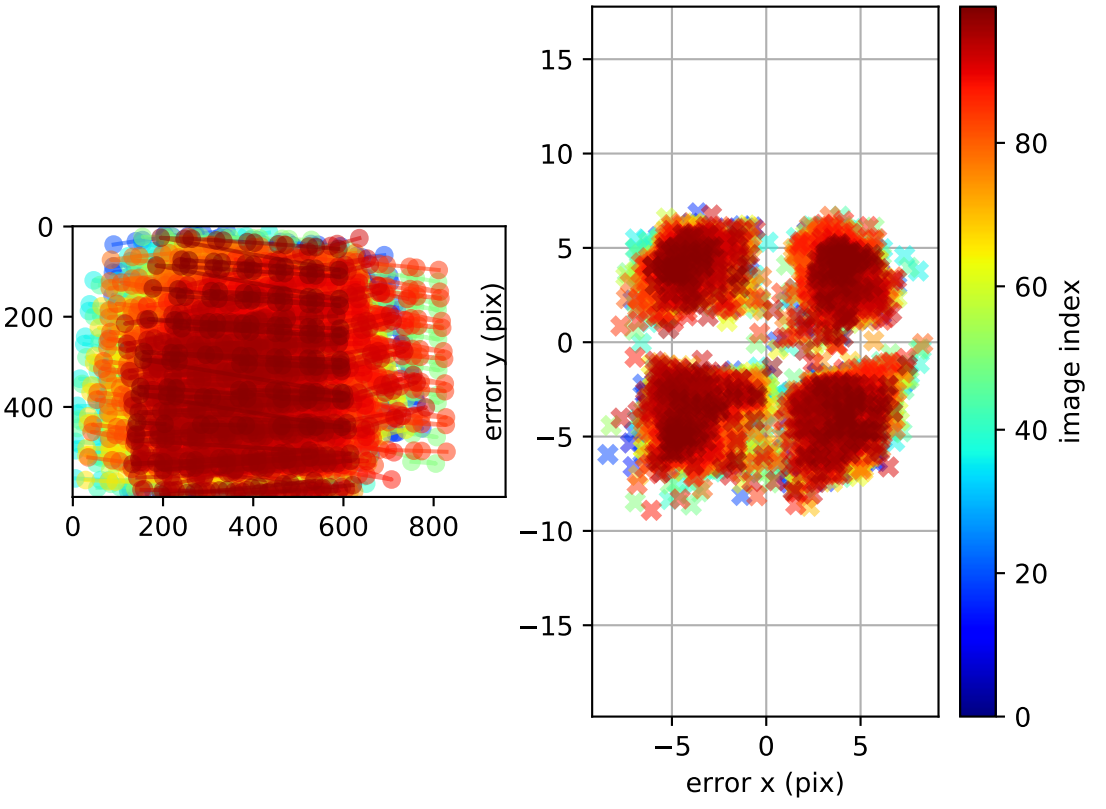

cam0: polar error
reprojection error (pixels)
polar angle (deg)
count
polar angle (deg)


cam0: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)
2
4
6
8
10
−100
0
100
0
500
1000
1500
2000
2500
3000


cam0: reprojection errors
0
200
400
0
200
400
600
800
error y (pix)
15
10
5
0
−5
−10
−15
−5
0
5
error x (pix)
80
60
40
20
0
image index


cam1: polar error
reprojection error (pixels)
polar angle (deg)
count
polar angle (deg)
0
2
4
6
8
10
0
10
20
30
40
0
500
1000
1500
2000
0
10
20
30
40


cam1: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)
10
8
6
4
2
−100
0
100
2000
1750
1500
1250
1000
750
500
250
0
−100
0
100


cam1: reprojection errors
0
200
400
0
200
400
600
800
error y (pix)
15
10
5
0
−5
−10
−15
−5
0
5
error x (pix)
80
60
40
20
0
image index