

Calibration results

=====

Camera-system parameters:

cam0 (/zedm/zed_node/right/image_rect_color):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.08394907 0.00700949 0.00030679 0.00237806] +- [0.00136774 0.00082165 0.00035581 0.0003081]

projection: [368.8201956 369.53822559 477.66069552 267.75087101] +- [0.34179786 0.3494873 0.40842122 0.98080604]

reprojection error: [0.000036, 0.000663] +- [2.443936, 2.404961]

cam1 (/zedm/zed_node/left/image_rect_color):

type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>

distortion: [-0.08008086 0.00282674 0.00037452 0.00411397] +- [0.00145566 0.00089814 0.00035844 0.00031355]

projection: [371.1897851 372.24933373 473.10494521 268.92000936] +- [0.34172994 0.35354457 0.4311722 0.97190486]

reprojection error: [-0.000143, 0.000638] +- [2.459346, 2.416266]

baseline T_1_0:

q: [0.00030123 -0.00011827 0.0016626 0.99999857] +- [0.00122411 0.00193981 0.00015521]

t: [0.04906147 -0.0008131 0.00097513] +- [0.00029584 0.00038349 0.00120735]

Target configuration

=====

Type: aprilgrid

Tags:

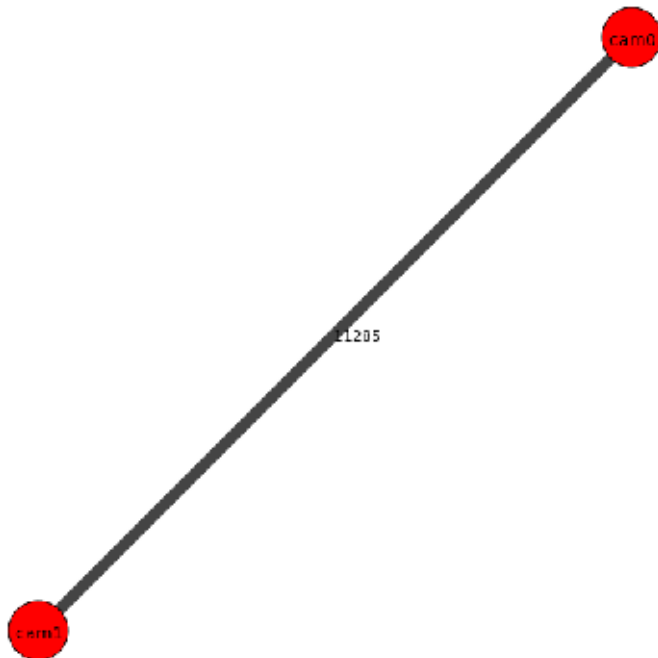
Rows: 6

Cols: 10

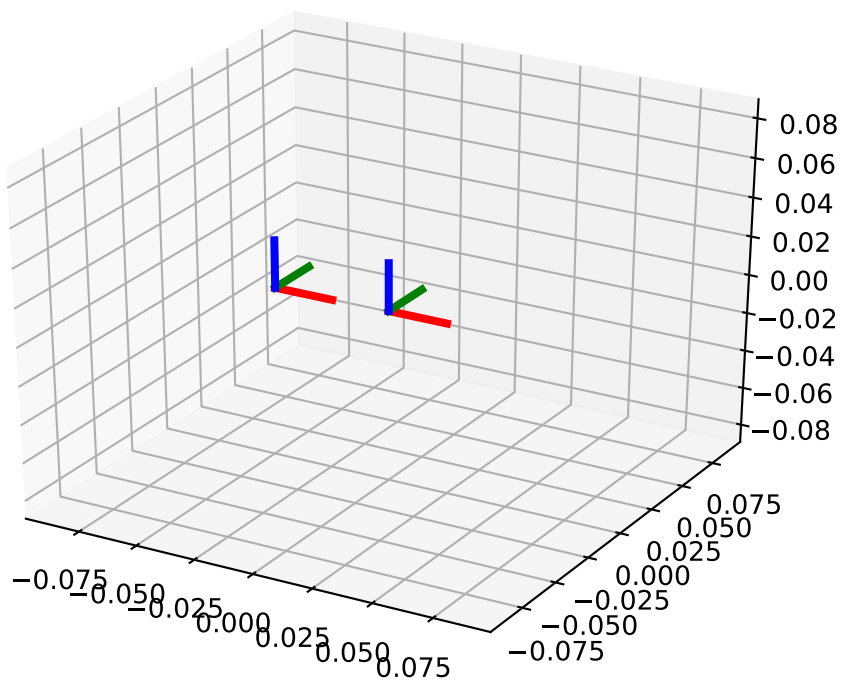
Size: 0.04 [m]

Spacing 0.00048 [m]

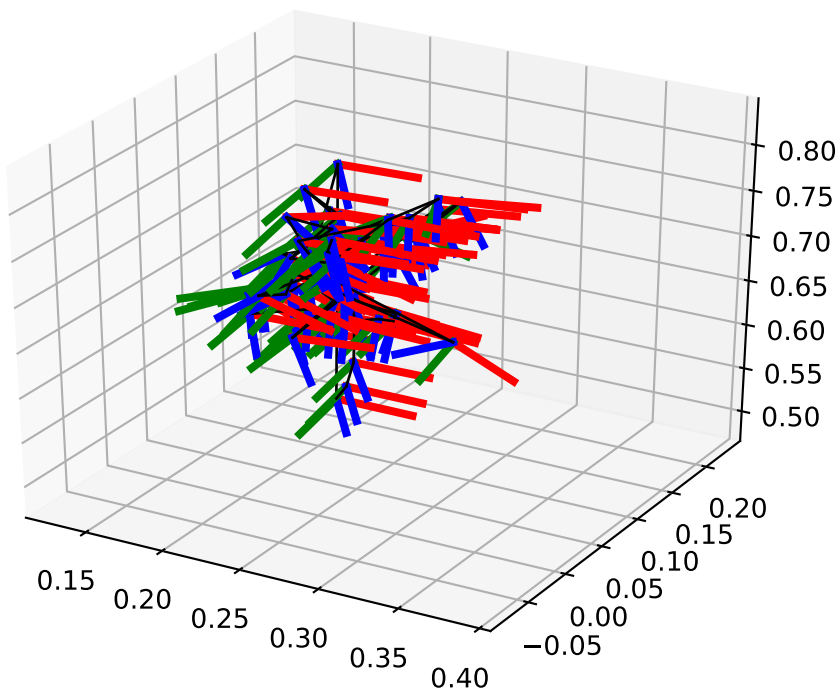
Inter-camera observations graph (edge weight=#mutual obs.)



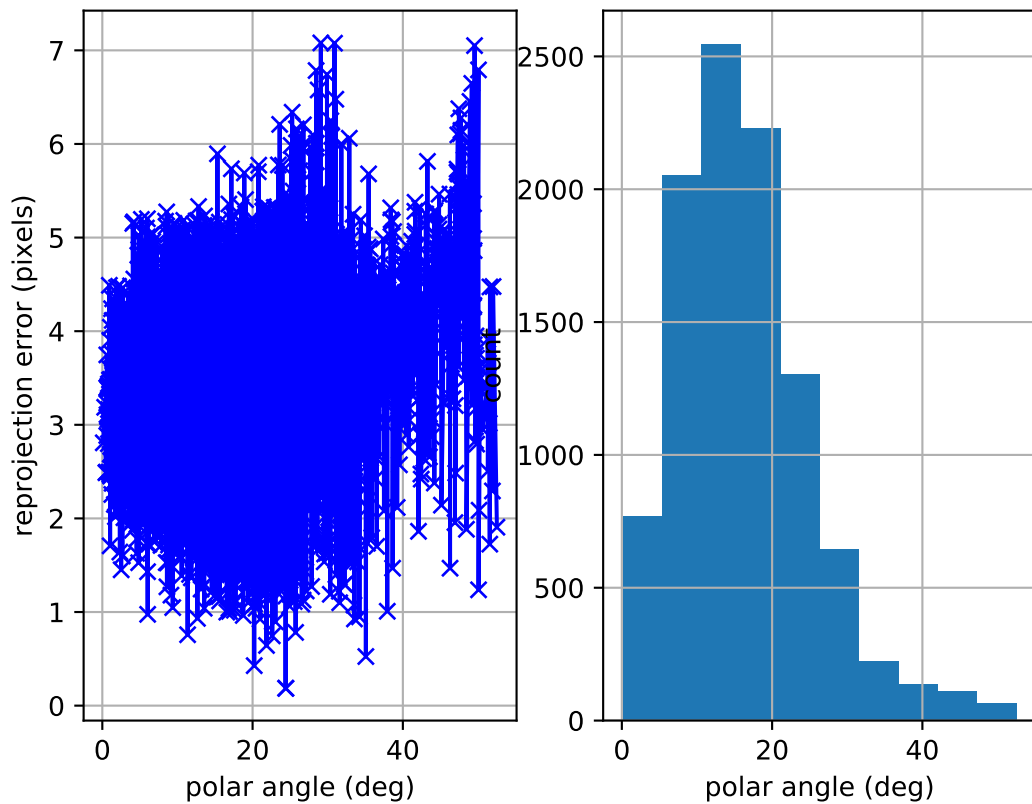
camera system



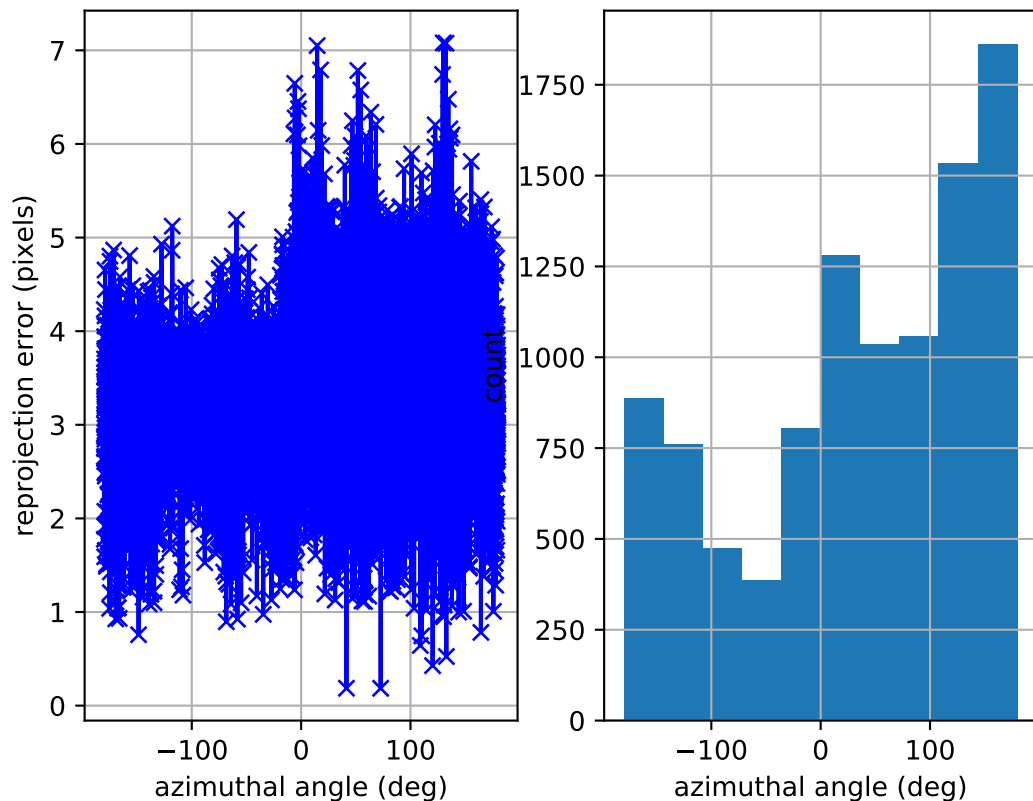
cam0: estimated poses



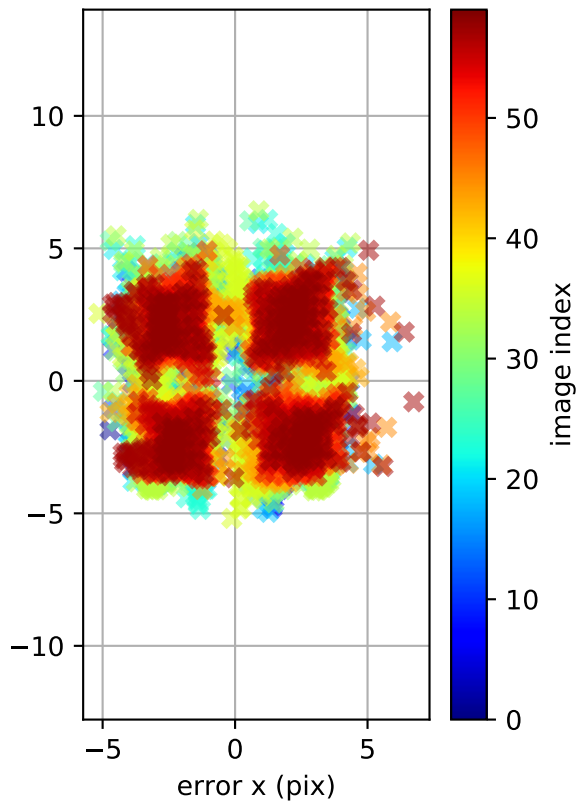
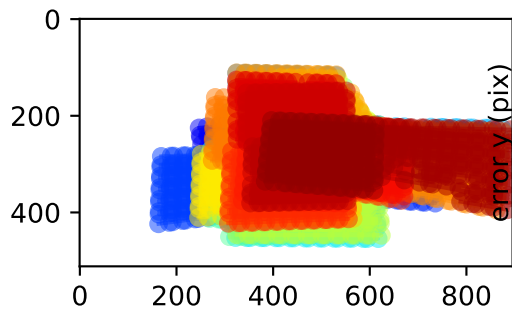
cam0: polar error



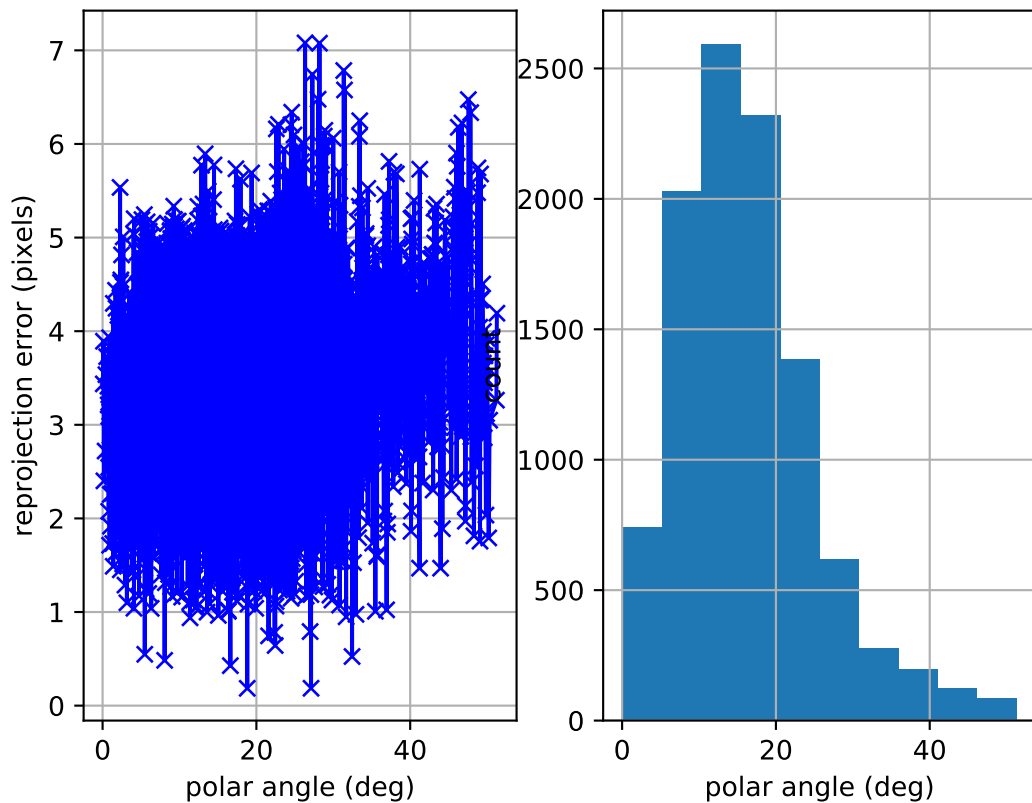
cam0: azimuthal error



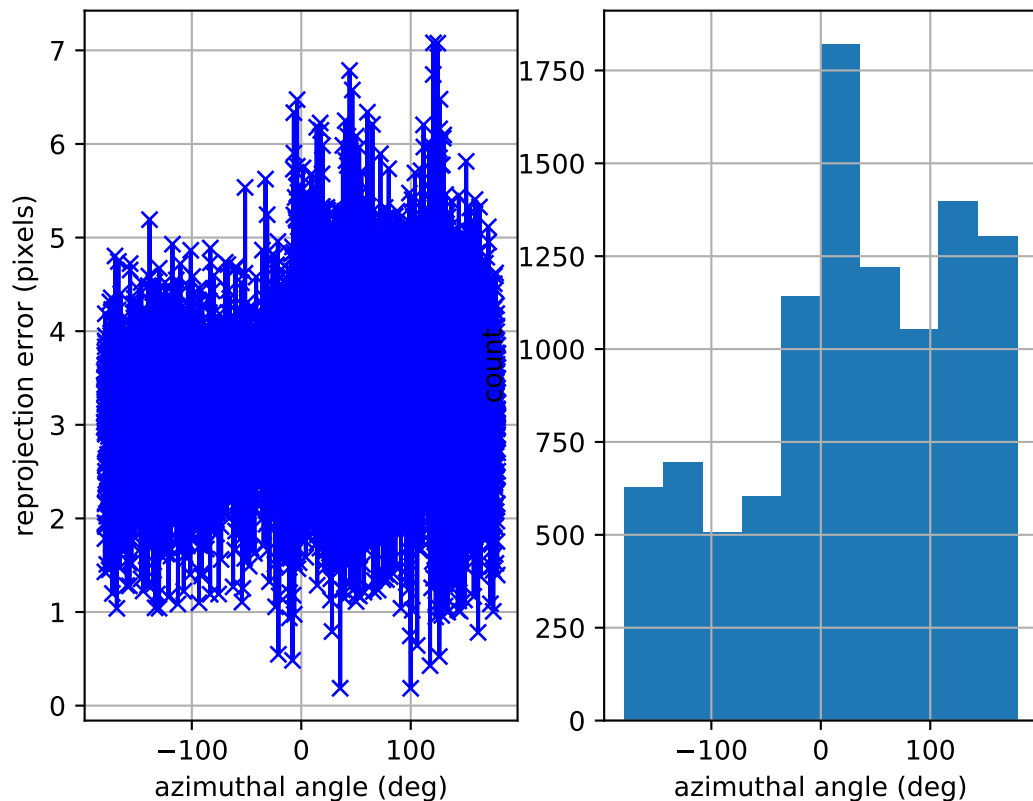
cam0: reprojection errors



cam1: polar error



cam1: azimuthal error



cam1: reprojection errors

