Calibration results
====================
Camera-system parameters:
cam0 (/b1/b1_front_cam/infra1/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00720806 -0.00544339 0.00051328 0.00075469] +- [0.00124156 0.00146223 0.00024697 0.0002834]
projection: [384.11039426 384.19238784 325.05252922 235.16816069] +- [0.36696333 0.36753938 0.35021311 0.31482462]
reprojection error: [0.000002, 0.000000] +- [0.134738, 0.100250]

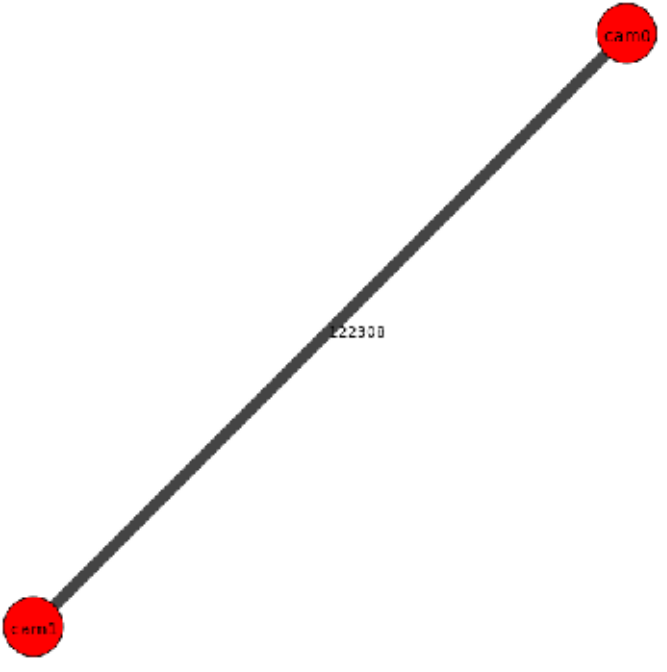
cam1 (/b1/b1_front_cam/infra2/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00620262 -0.0037351   0.0004083   0.00082286] +- [0.00127626 0.001272   0.00024705 0.00030981]
projection: [383.41242925 383.41880187 323.85446191 236.0895558] +- [0.3725725 0.37106298 0.36414933 0.33201445]
reprojection error: [-0.000002, 0.000000] +- [0.141454, 0.111007]

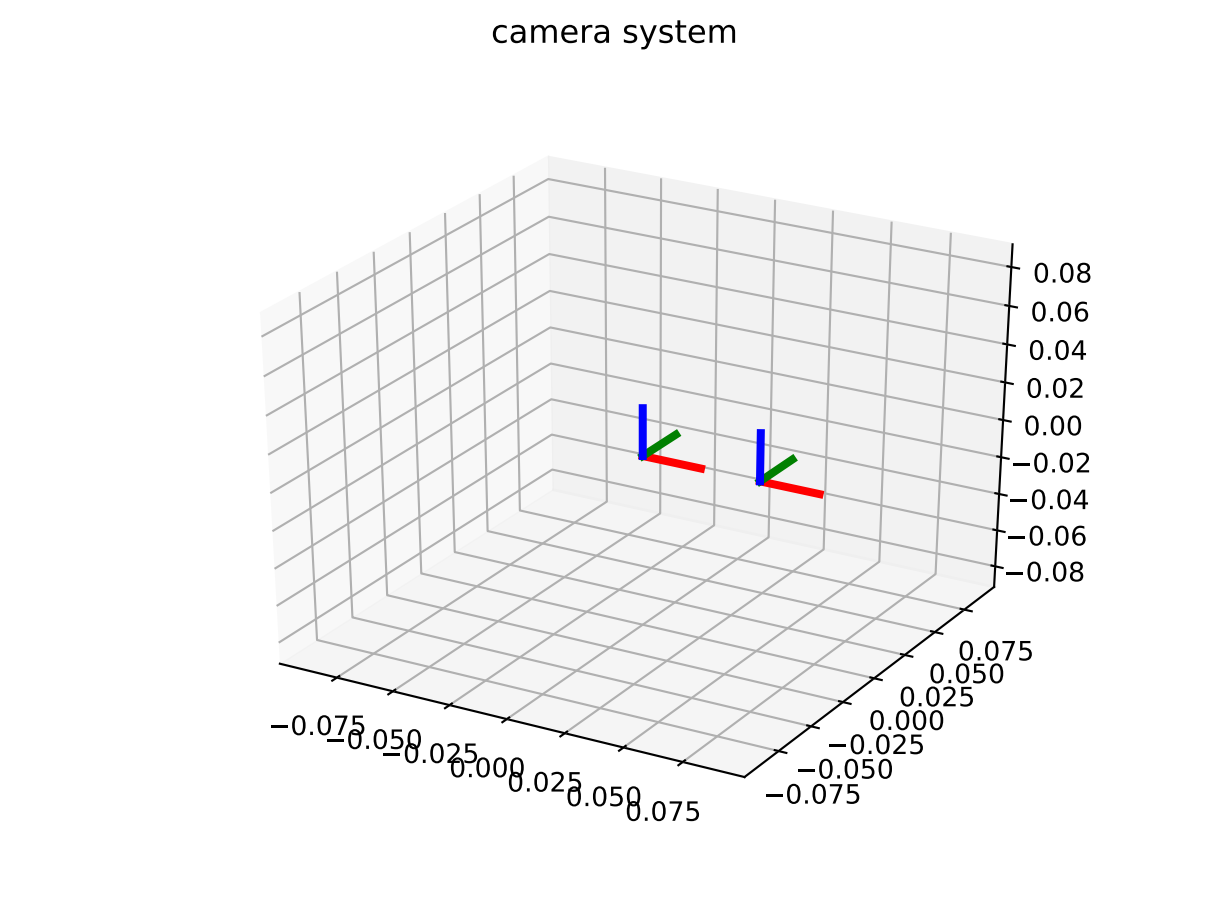
baseline T_1_0:
q: [-0.00022904 -0.00055939 -0.00001847 0.99999982] +- [0.00068943 0.00088931 0.00011144]
t: [-0.05023071 -0.00011322 0.00017855] +- [0.00003747 0.00003041 0.00008456]

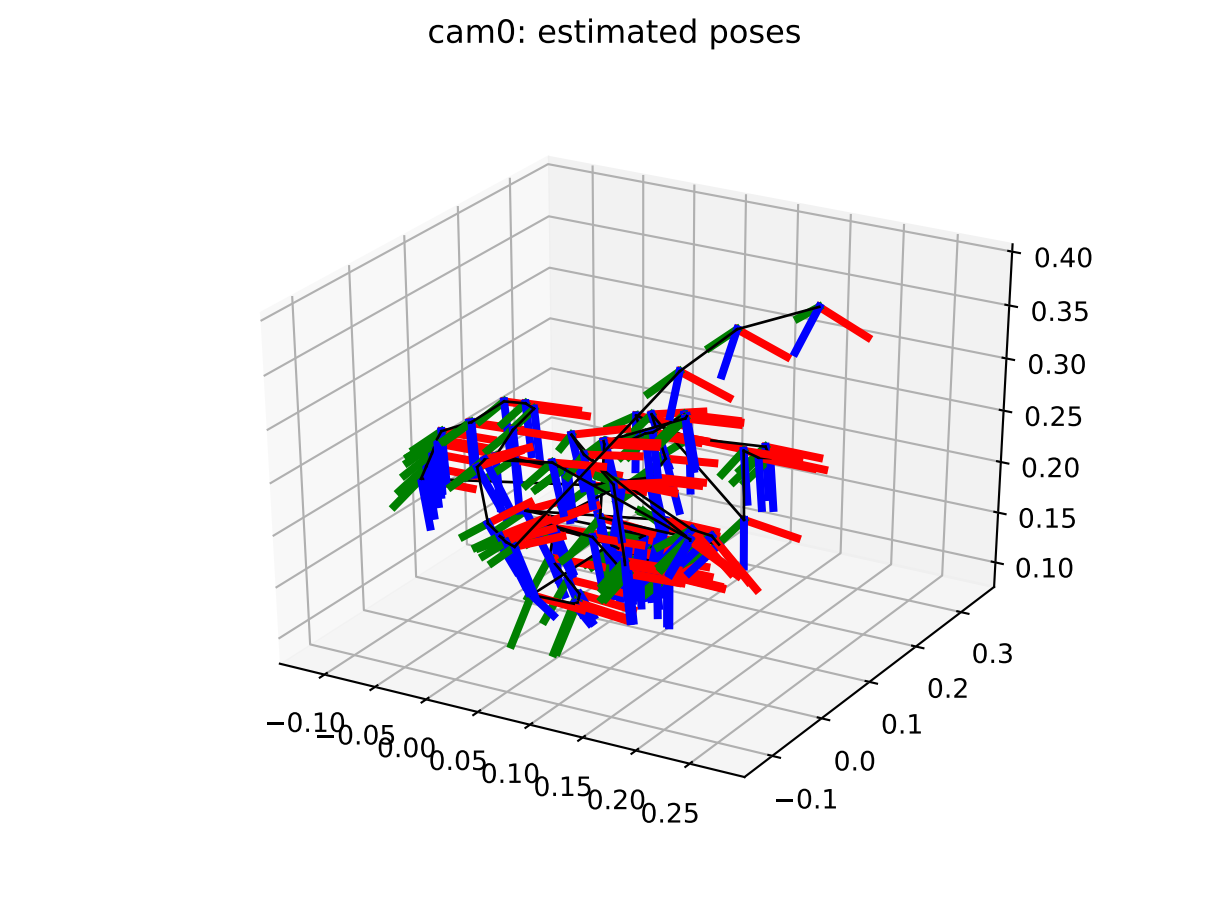
Target configuration
====================

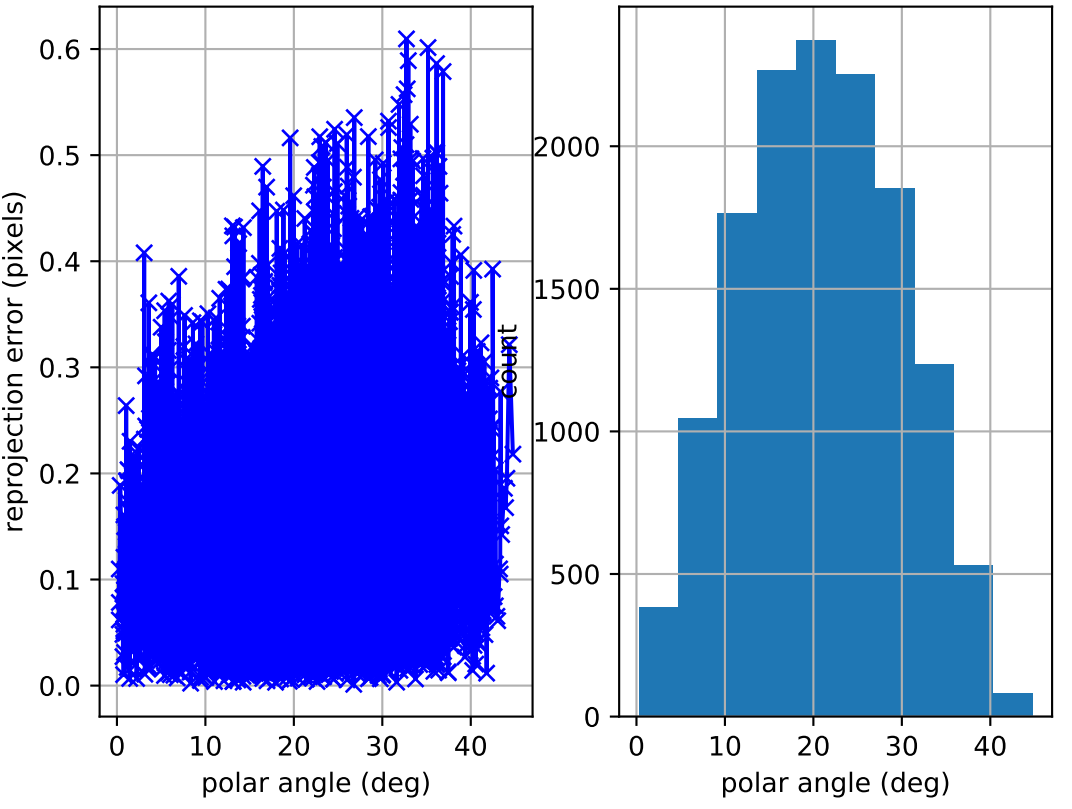
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.02 [m]
Spacing 0.006 [m]

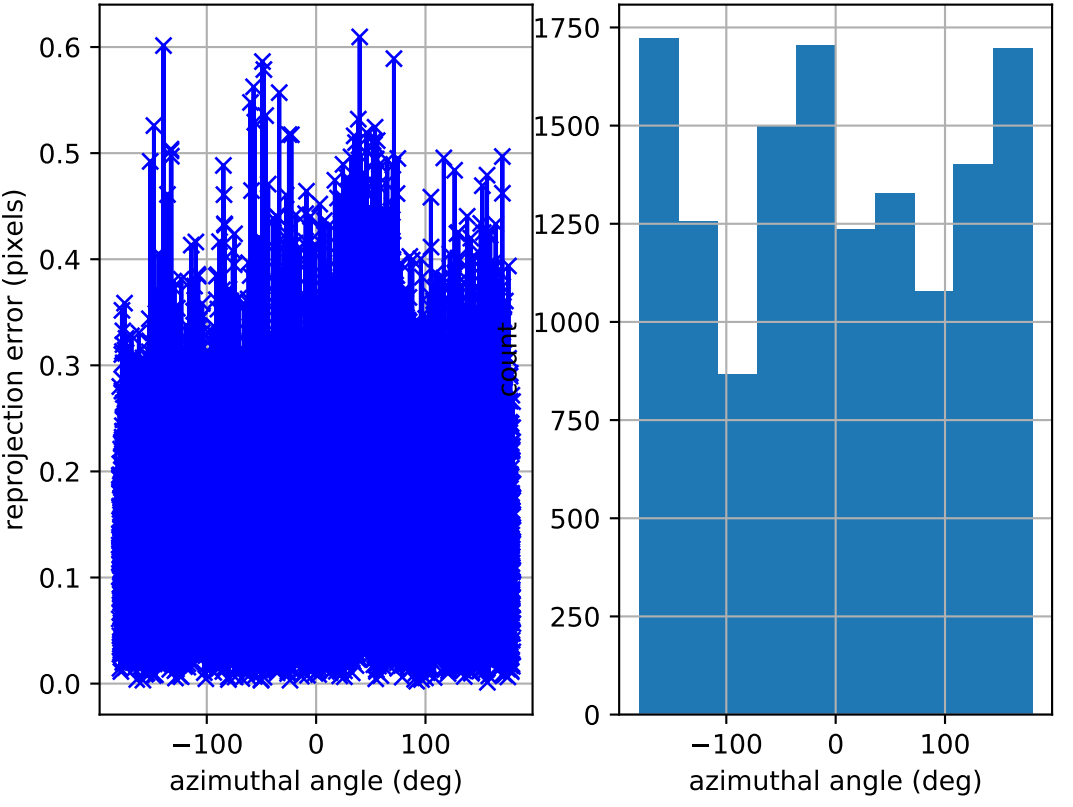
Inter-camera observations graph (edge weight=#mutual obs.)

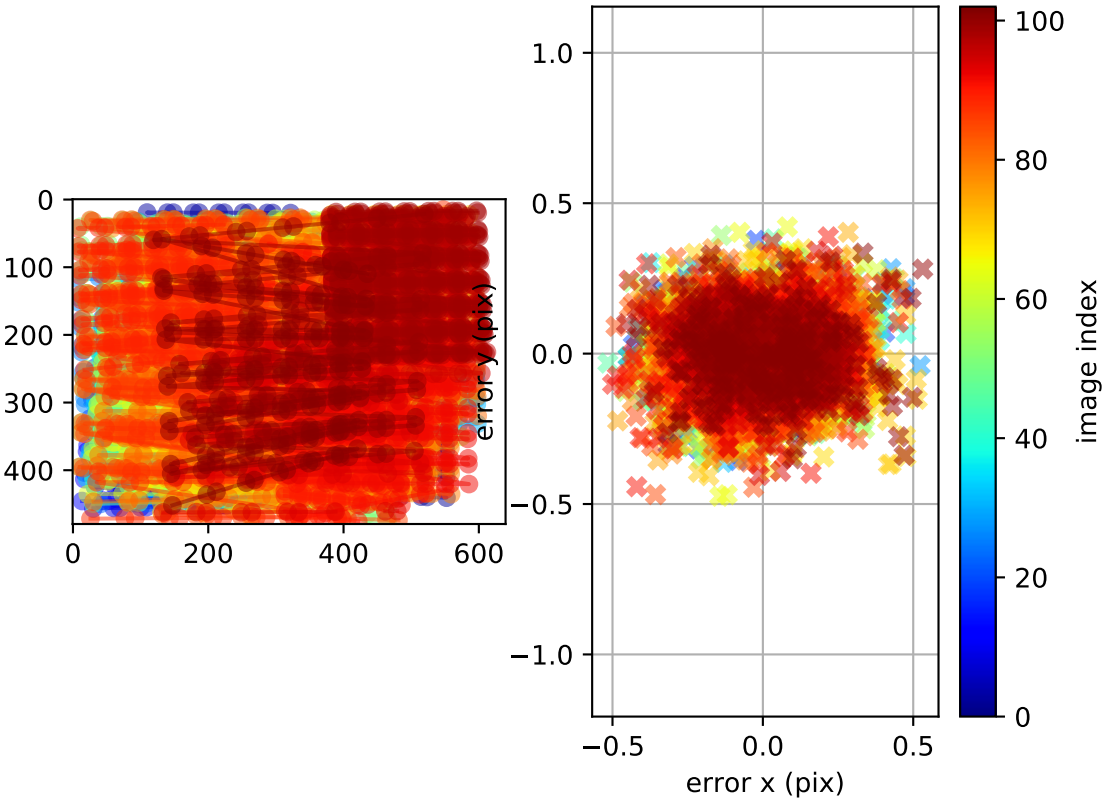


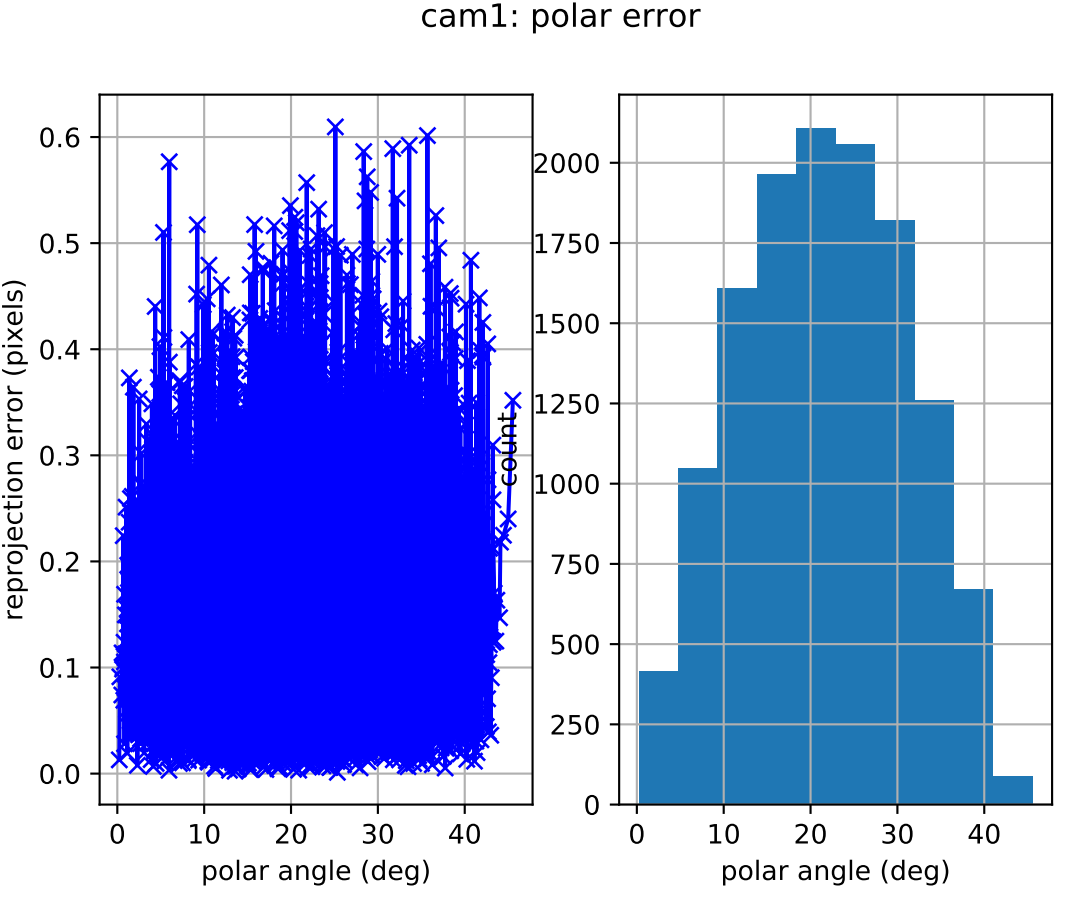

camera system
0.08
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
−0.08
0.075
0.050
0.025
0.000
−0.025
−0.050
−0.075
−0.075
−0.050
−0.025
0.000
0.025
0.050
0.075

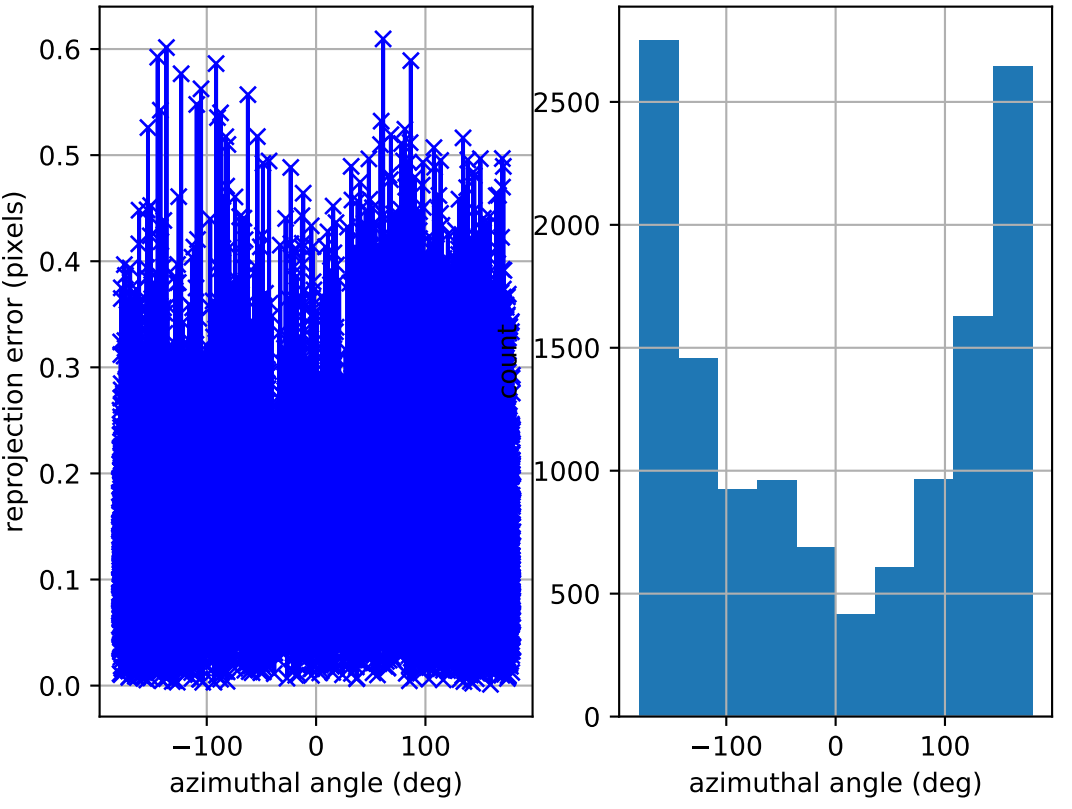

cam0: estimated poses
0.40
0.35
0.30
0.25
0.20
0.15
0.10
0.3
0.2
0.1
0.0
−0.1
−0.10
−0.05
0.00
0.05
0.10
0.15
0.20
0.25

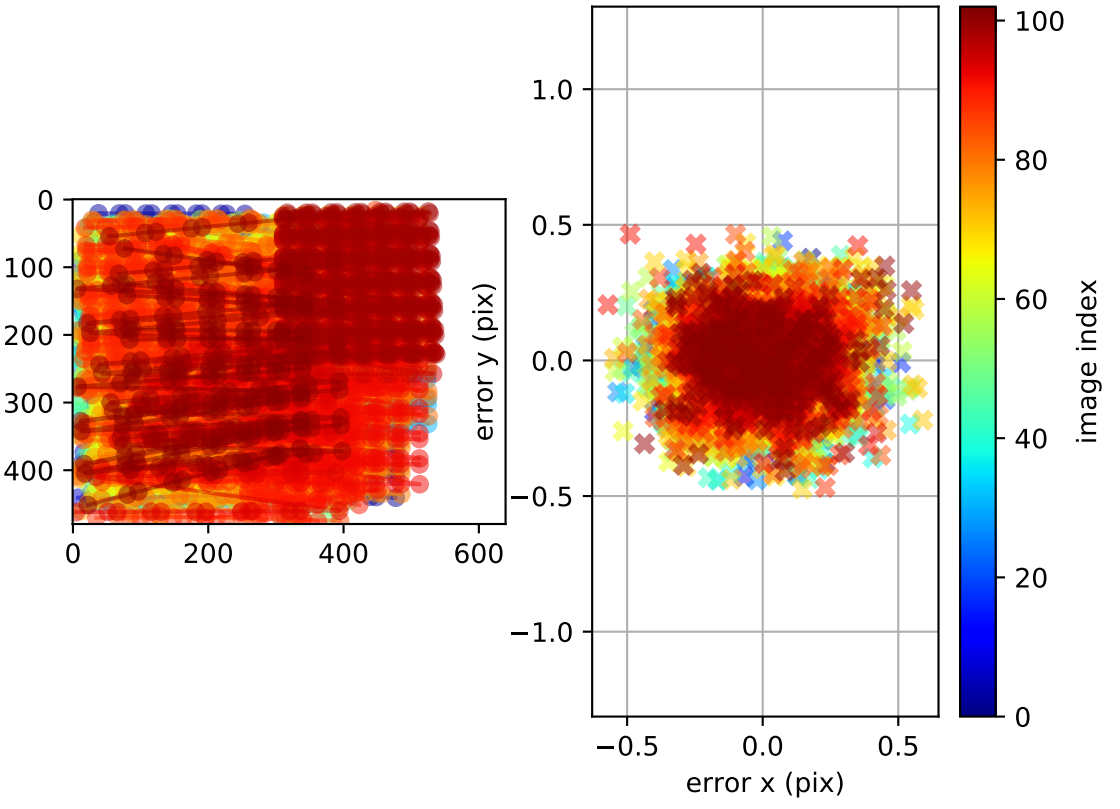

cam0: polar error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
0.6
0
10
20
30
40
polar angle (deg)
count
0
500
1000
1500
2000
0
10
20
30
40
polar angle (deg)

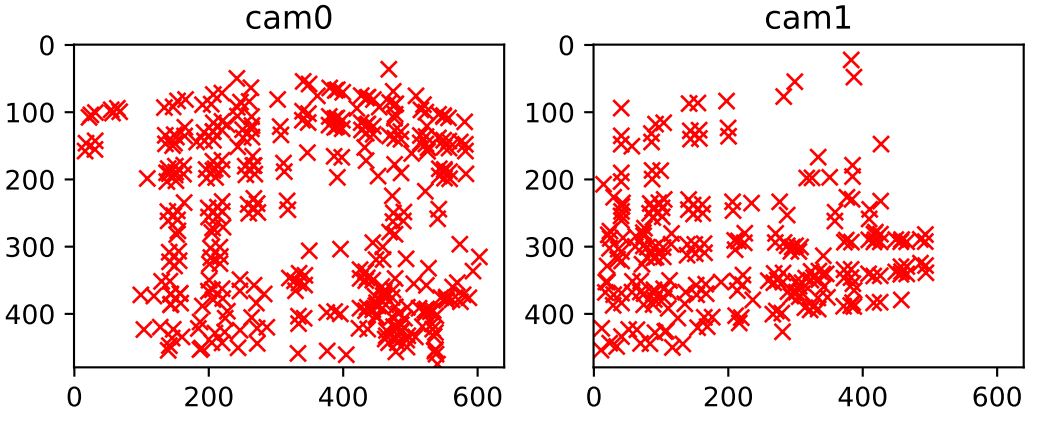

cam0: azimuthal error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
0.6
−100
0
100
azimuthal angle (deg)
count
0
250
500
750
1000
1250
1500
1750
−100
0
100
azimuthal angle (deg)


cam0: reprojection errors
0
100
200
300
400
0
200
400
600
error y (pix)
1.0
0.5
0.0
−0.5
−1.0
−0.5
0.0
0.5
error x (pix)
100
80
60
40
20
0
image index


cam1: polar error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
0.6
0
10
20
30
40
polar angle (deg)
count
0
250
500
750
1000
1250
1500
1750
2000
0
10
20
30
40
polar angle (deg)


cam1: azimuthal error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
0.6
−100
0
100
azimuthal angle (deg)
count
0
500
1000
1500
2000
2500
−100
0
100
azimuthal angle (deg)


cam1: reprojection errors
0
100
200
300
400
0
200
400
600
error y (pix)
1.0
0.5
0.0
−0.5
−1.0
−0.5
0.0
0.5
error x (pix)
100
80
60
40
20
0
image index


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