Calibration results
====================
Camera-system parameters:
cam0 (/camera/infra1/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00085389 -0.00194579 0.00017296 0.000851] +- [0.00215987 0.00151322 0.00029279 0.00044794]
projection: [421.38000086 422.45094804 420.23362216 243.53281744] +- [0.16854094 0.17823564 0.49499623 0.20492708]
reprojection error: [0.000007, 0.000004] +- [0.059471, 0.041357]

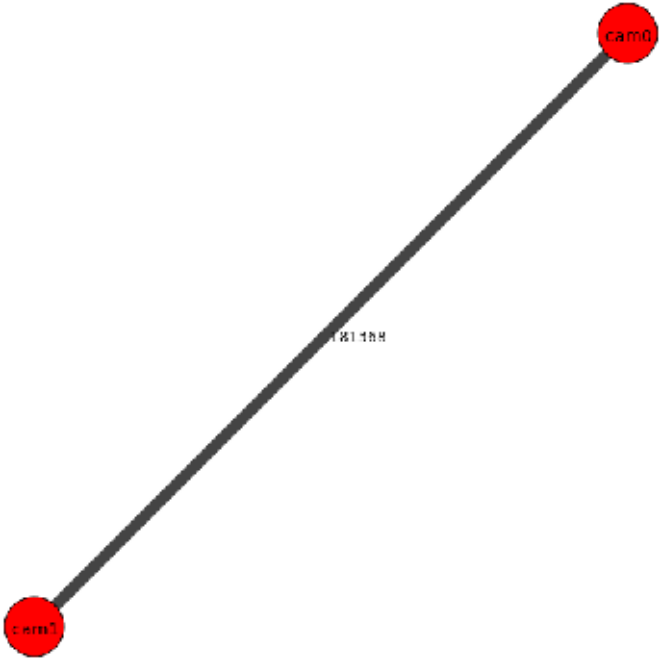
cam1 (/camera/infra2/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.0026402 -0.00465222 0.00002009 0.00061086] +- [0.00217717 0.00239173 0.00029063 0.00043453]
projection: [421.67642673 422.64905503 420.52476853 243.56185881] +- [0.18089043 0.16553414 0.47360926 0.2064673]
reprojection error: [-0.000009, 0.000003] +- [0.051913, 0.043501]

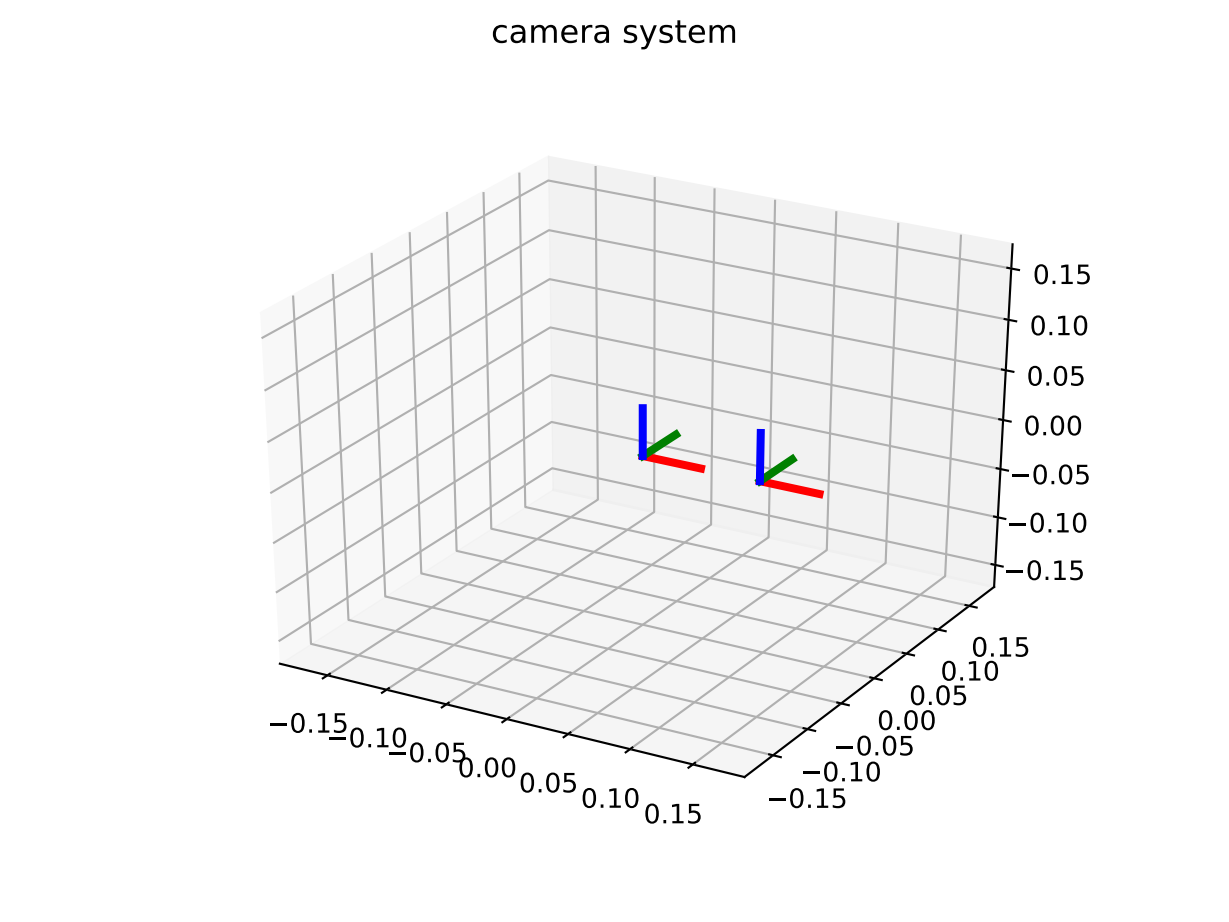
baseline T_1_0:
q: [-0.00025313 0.0000465 -0.00002066 0.99999997] +- [0.00091496 0.00226263 0.00016132]
t: [-0.09510432 -0.00003643 -0.00003428] +- [0.00011068 0.00008235 0.00030441]

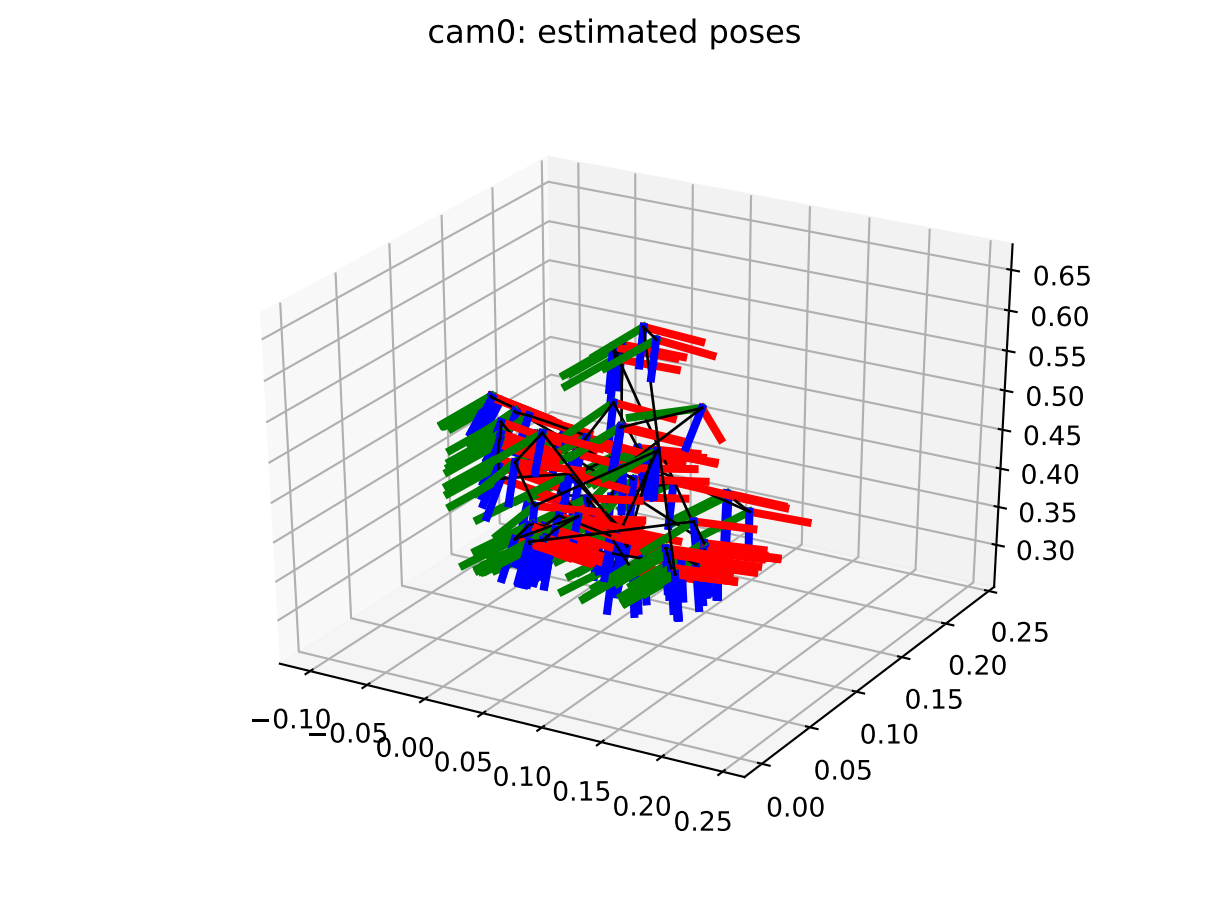
Target configuration
====================

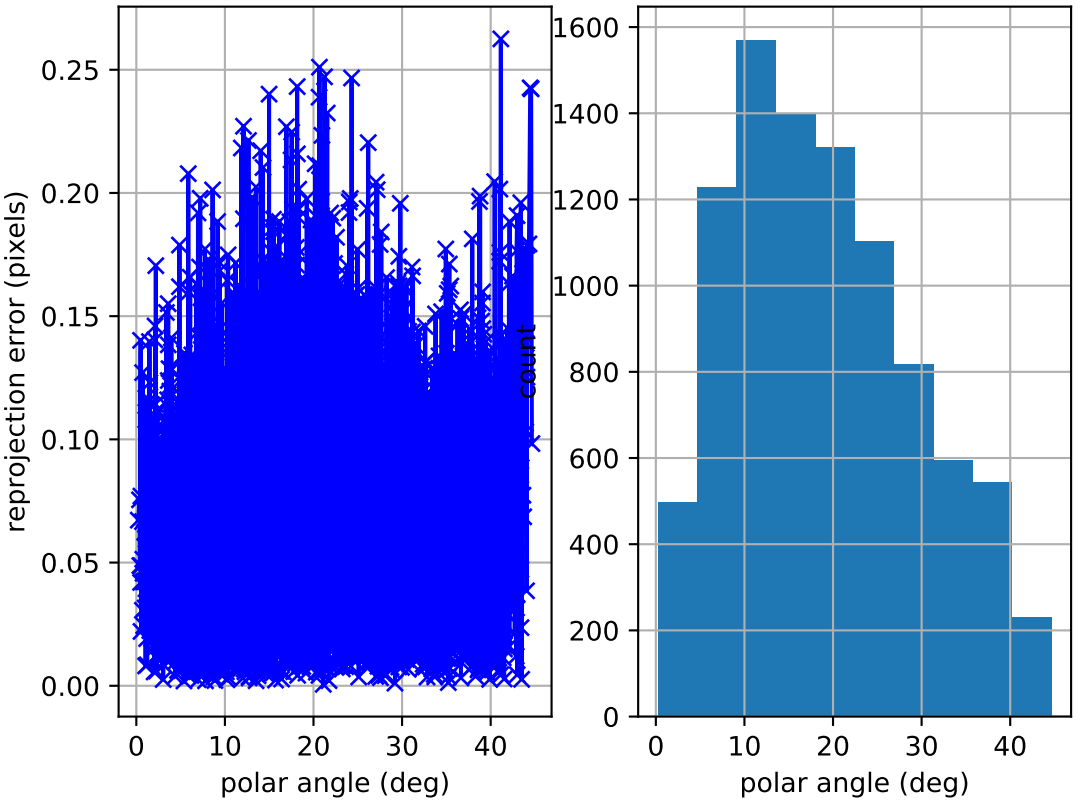
Type: checkerboard
Rows
Count: 11
Distance: 0.02 [m]
Cols
Count: 8
Distance: 0.02 [m]

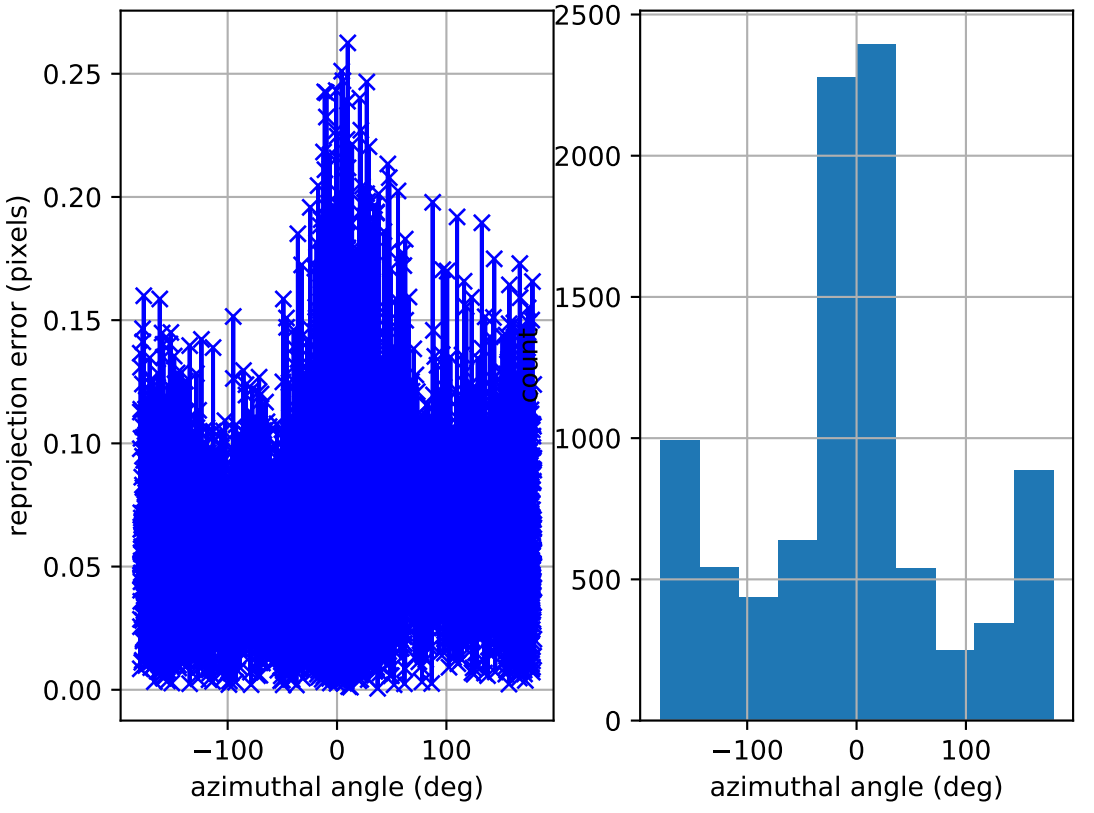
Inter-camera observations graph (edge weight=#mutual obs.)

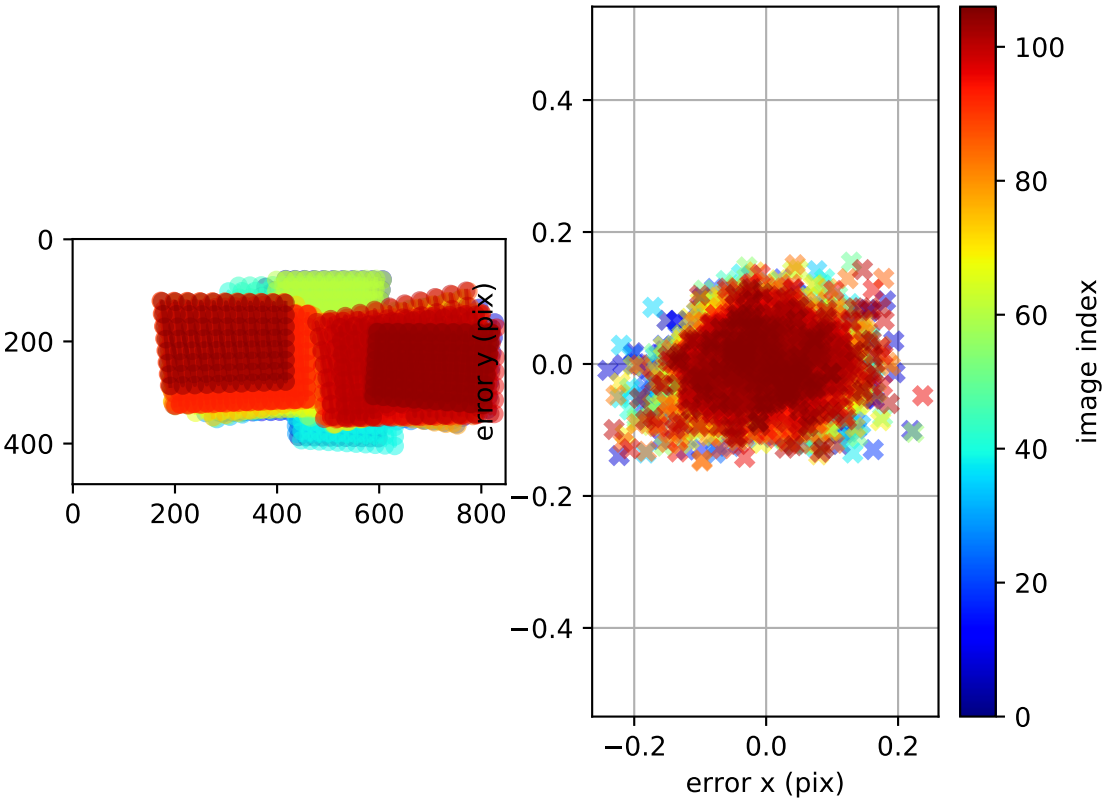


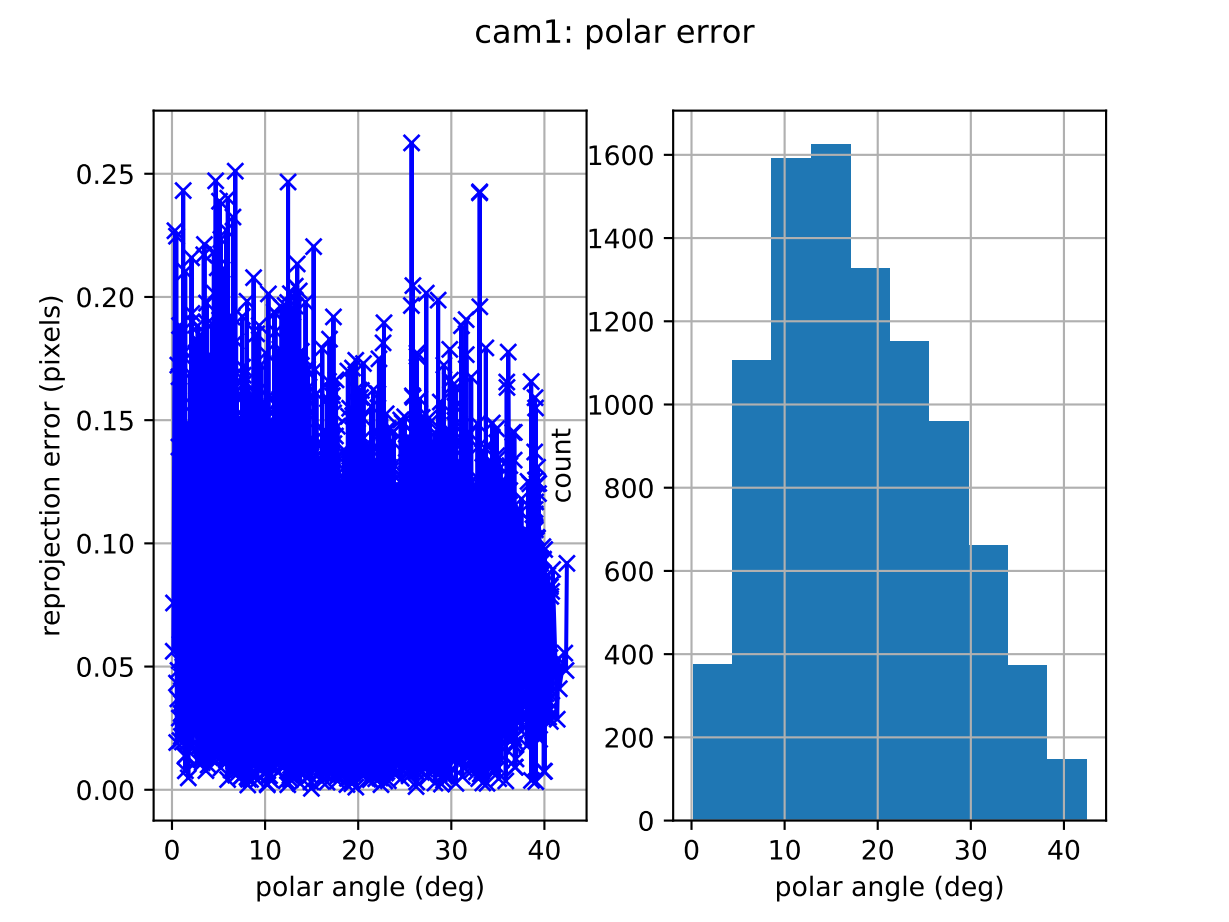

camera system
0.15
0.10
0.05
0.00
−0.05
−0.10
−0.15
−0.15
−0.10
−0.05
0.00
0.05
0.10
0.15
0.15
0.10
0.05
0.00
−0.05
−0.10
−0.15

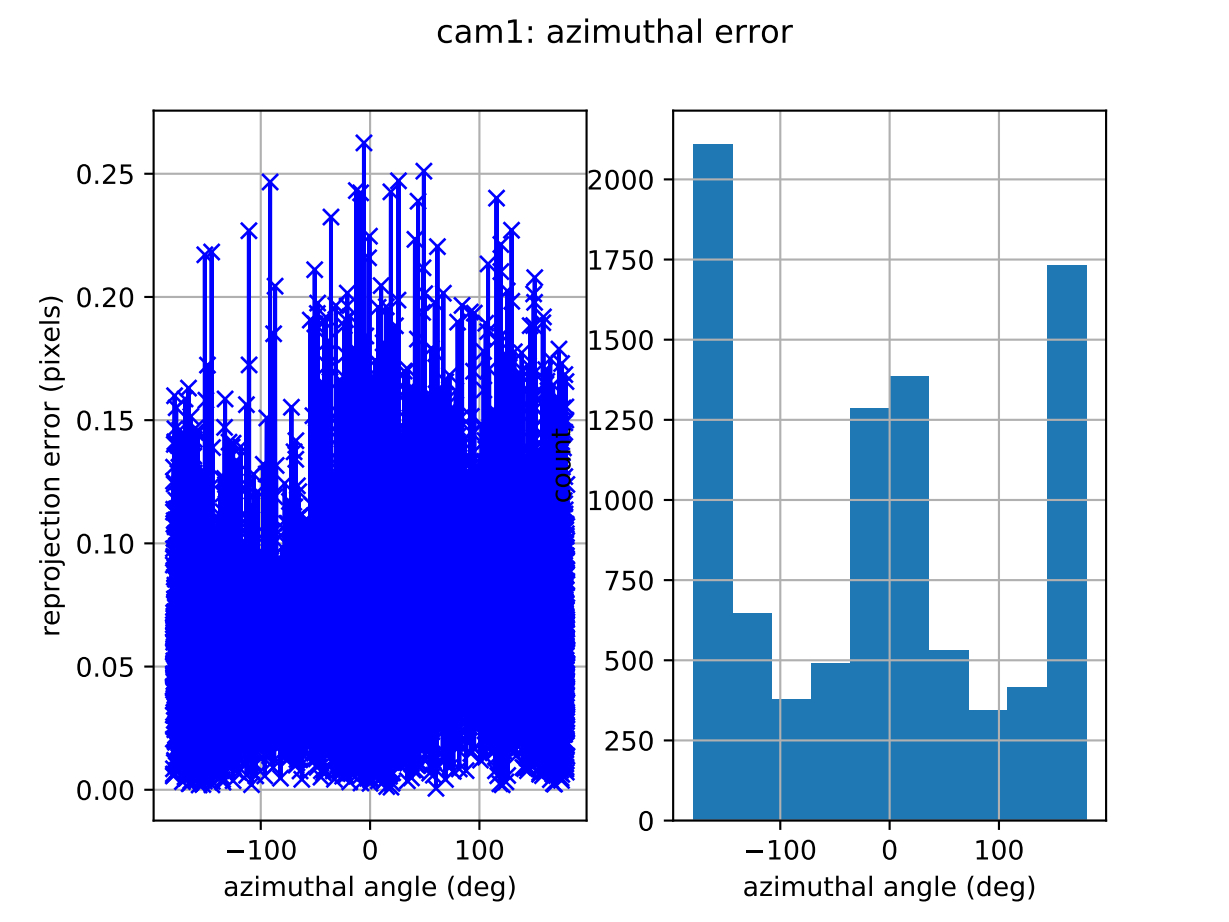

cam0: estimated poses
0.65
0.60
0.55
0.50
0.45
0.40
0.35
0.30
0.25
0.20
0.15
0.10
0.05
0.00
−0.10
−0.05
0.00
0.05
0.10
0.15
0.20
0.25

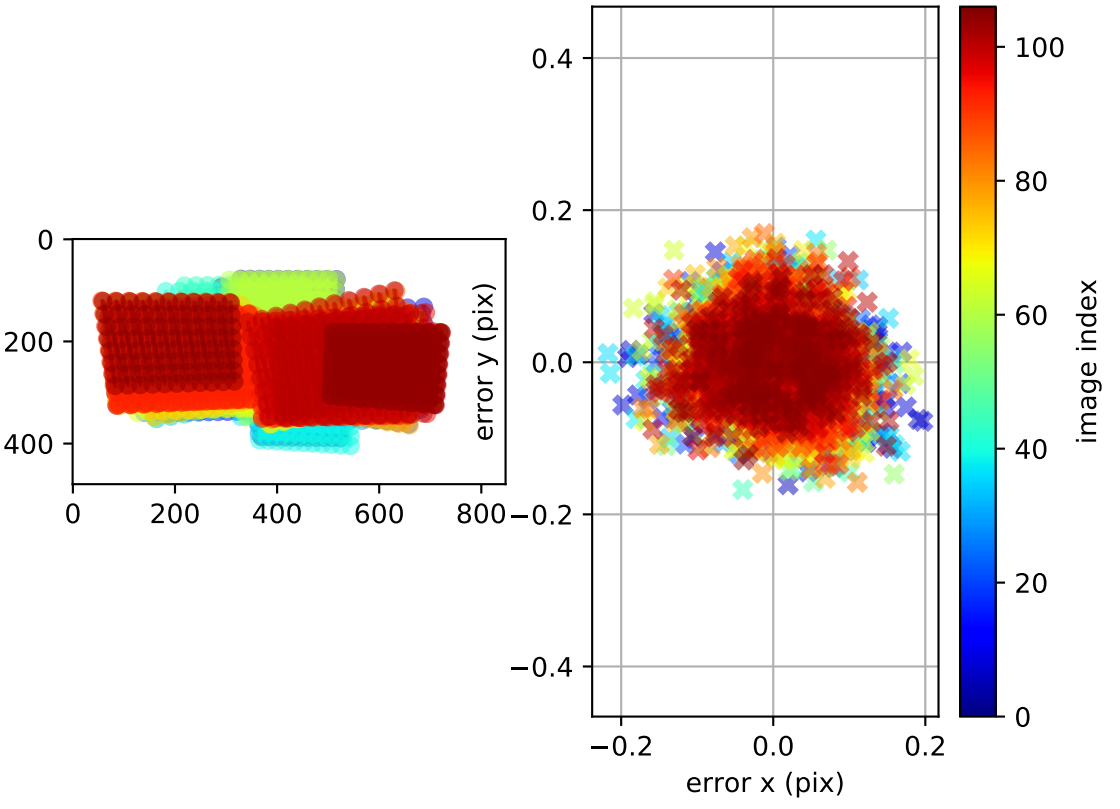

cam0: polar error
reprojection error (pixels)
0.25
0.20
0.15
0.10
0.05
0.00
0
10
20
30
40
polar angle (deg)
count
1600
1400
1200
1000
800
600
400
200
0
0
10
20
30
40
polar angle (deg)

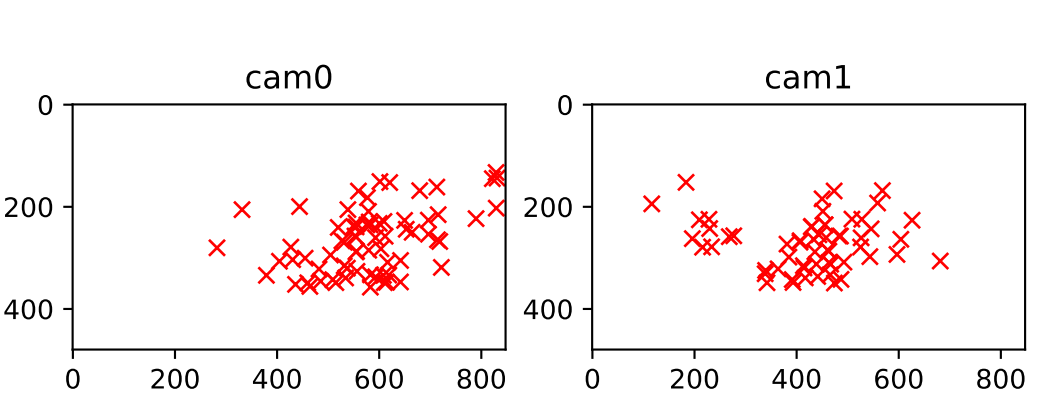

cam0: azimuthal error
reprojection error (pixels)
0.25
0.20
0.15
0.10
0.05
0.00
−100
0
100
azimuthal angle (deg)
count
2500
2000
1500
1000
500
0
−100
0
100
azimuthal angle (deg)


cam0: reprojection errors
0
200
400
0
200
400
600
800
error y (pix)
0.4
0.2
0.0
−0.2
−0.4
−0.2
0.0
0.2
error x (pix)
100
80
60
40
20
0
image index


cam1: polar error
reprojection error (pixels)
0.25
0.20
0.15
0.10
0.05
0.00
0
10
20
30
40
polar angle (deg)
count
1600
1400
1200
1000
800
600
400
200
0
0
10
20
30
40
polar angle (deg)


cam1: azimuthal error
reprojection error (pixels)
0.25
0.20
0.15
0.10
0.05
0.00
−100
0
100
azimuthal angle (deg)
count
2000
1750
1500
1250
1000
750
500
250
0
−100
0
100
azimuthal angle (deg)


cam1: reprojection errors
0
200
400
0
200
400
600
800
error y (pix)
0.4
0.2
0.0
−0.2
−0.4
−0.2
0.0
0.2
error x (pix)
100
80
60
40
20
0
image index


Location of removed outlier corners
cam0
cam1
0
200
400
600
800