Calibration results
====================
Camera-system parameters:
cam0 (/color):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.11586722 -0.23927257 -0.00077789 -0.00106366] +- [0.00262334 0.0057354 0.00021144 0.00024647]
projection: [907.15586962 906.99751611 632.0719471 358.64087959] +- [0.10944773 0.10694917 0.32742728 0.20774262]
reprojection error: [0.000425, -0.000104] +- [0.219455, 0.167223]

cam1 (/infra_left):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00342385 0.00022603 0.00082758 0.00119861] +- [0.00396507 0.00975429 0.00033732 0.0004711]
projection: [425.53917012 426.21360306 432.39220833 233.71489874] +- [0.07949999 0.08486387 0.48454302 0.33350283]
reprojection error: [-0.000022, -0.000067] +- [0.183752, 0.138126]

cam2 (/infra_right):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00165636 0.00430624 0.000569   0.00245598] +- [0.00315229 0.00663264 0.00032619 0.00047414]
projection: [427.27067271 427.78947664 434.18647094 233.88537654] +- [0.08493593 0.10651005 0.48668187 0.33735899]
reprojection error: [-0.000363, -0.000089] +- [0.178506, 0.140814]

baseline T_1_0:
q: [0.00071883 0.00440653 -0.00724739 0.99996377] +- [0.00086529 0.00134875 0.00007856]
t: [-0.01602118 0.00031772 -0.00256467] +- [0.00022215 0.00022219 0.00027853]

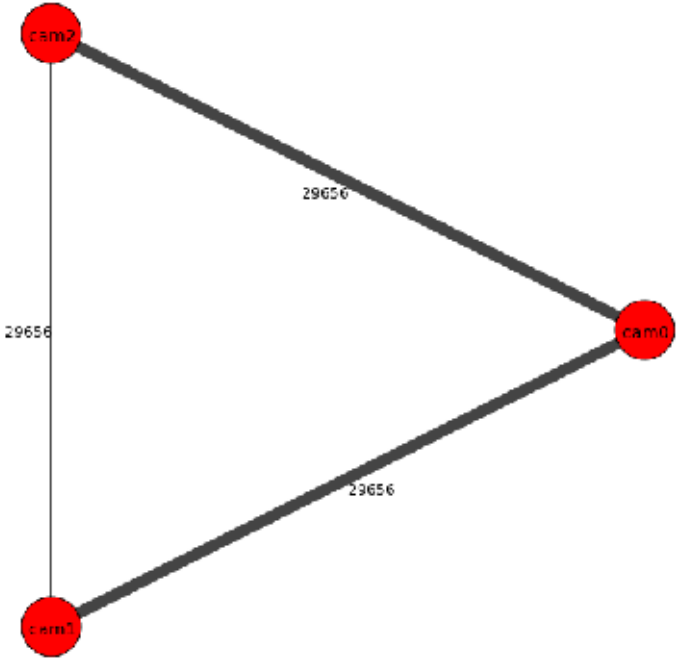
baseline T_2_1:
q: [-0.00037224 0.00192659 -0.00001136 0.99999807] +- [0.00111223 0.00175195 0.00010613]
t: [-0.05014043 0.00017618 0.00066283] +- [0.0002875 0.00028745 0.00039773]

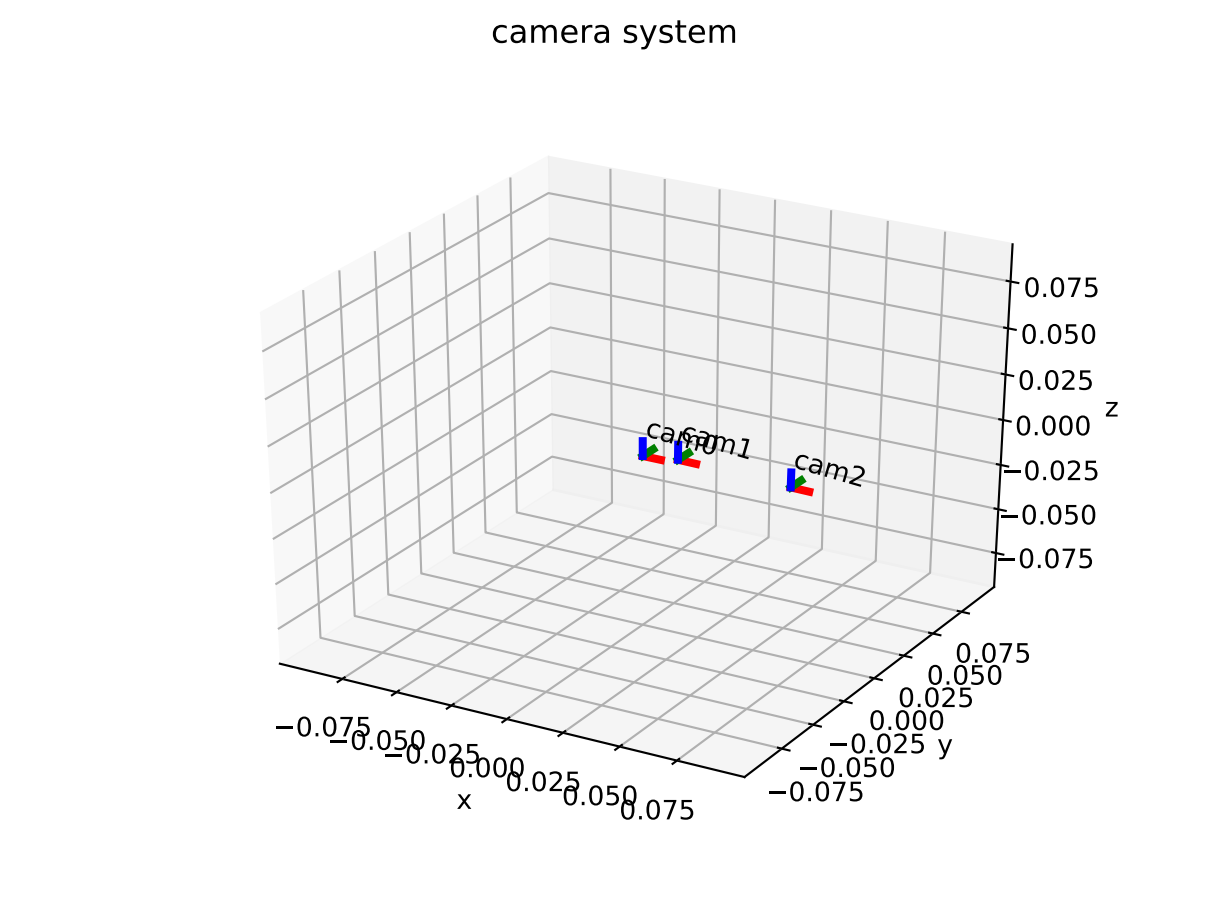
Target configuration
====================

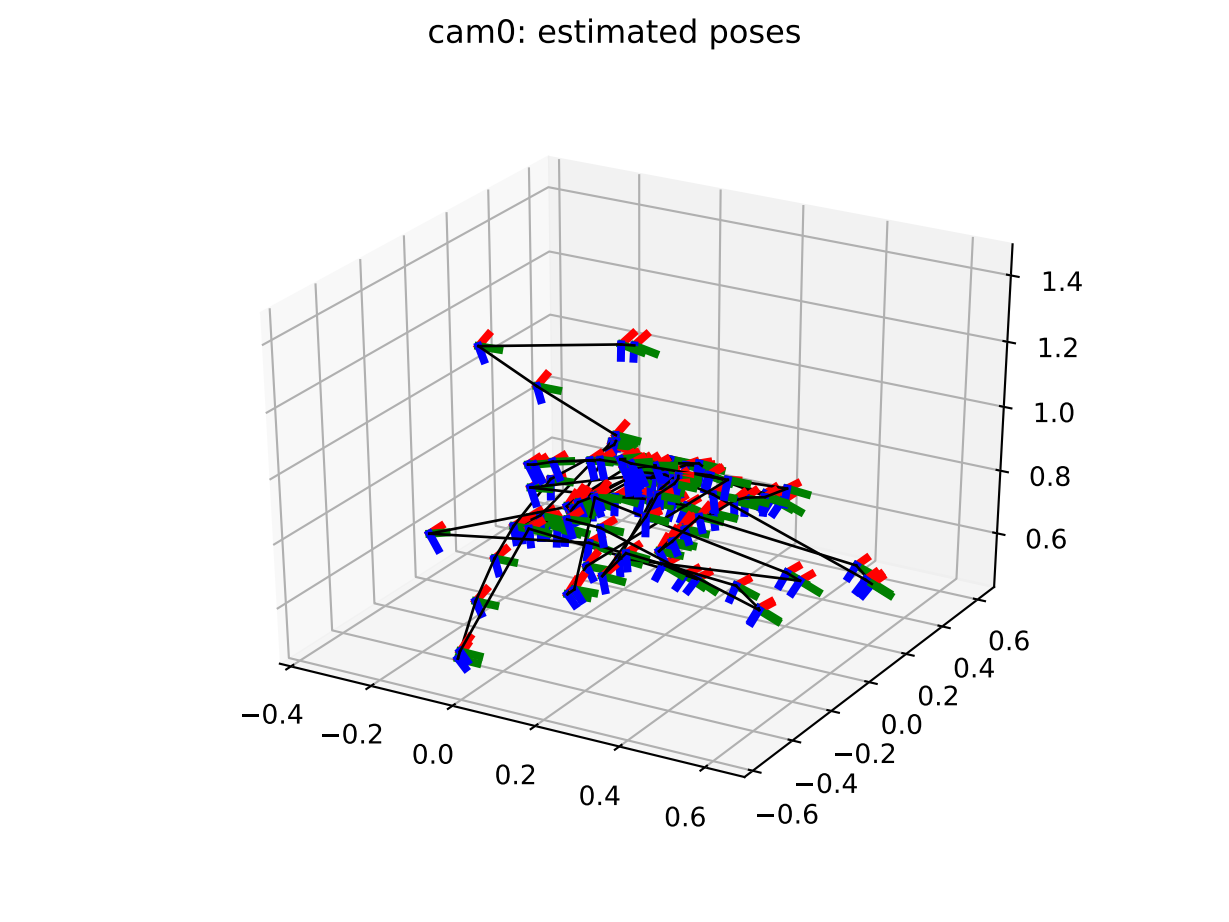
Type: checkerboard

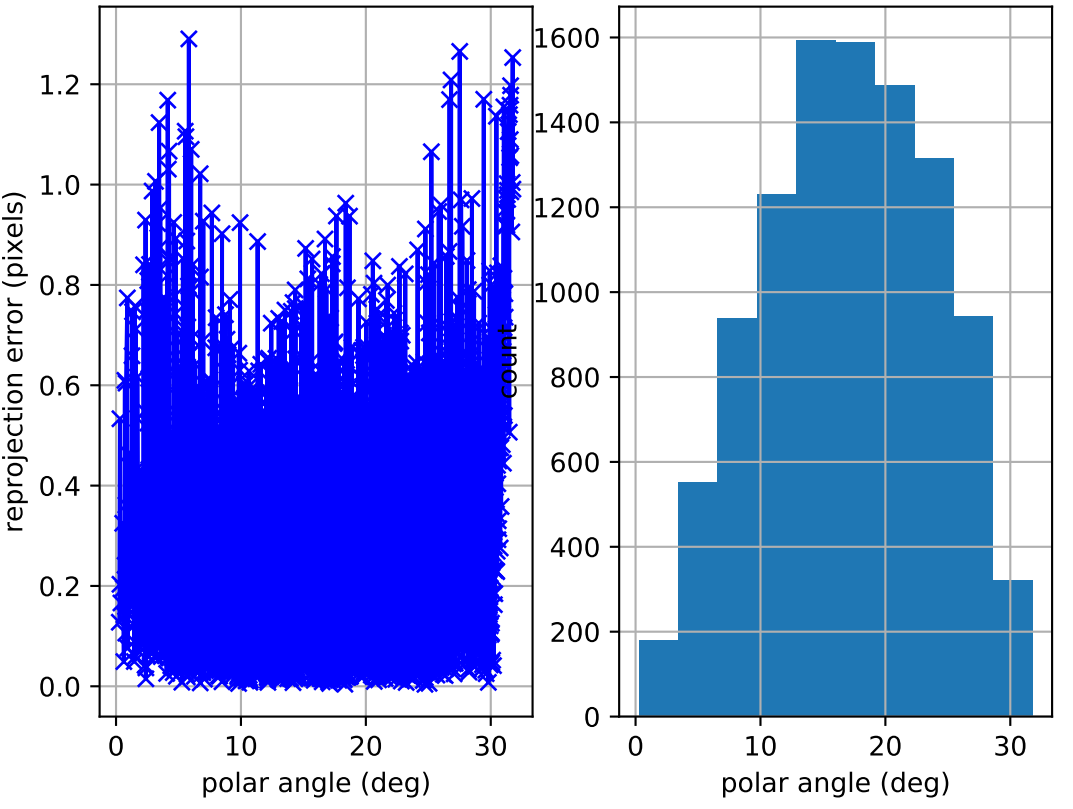
Rows
Count: 8
Distance: 0.03 [m]
Cols
Count: 11
Distance: 0.03 [m]

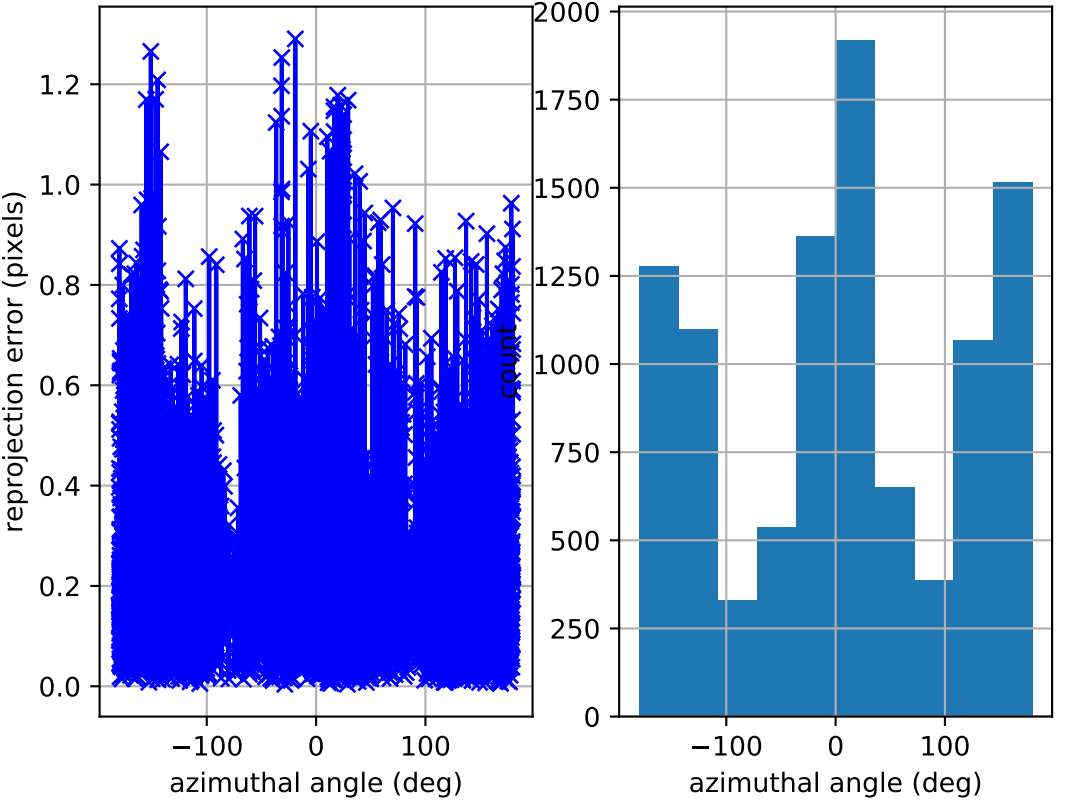
Inter-camera observations graph (edge weight=#mutual obs.)

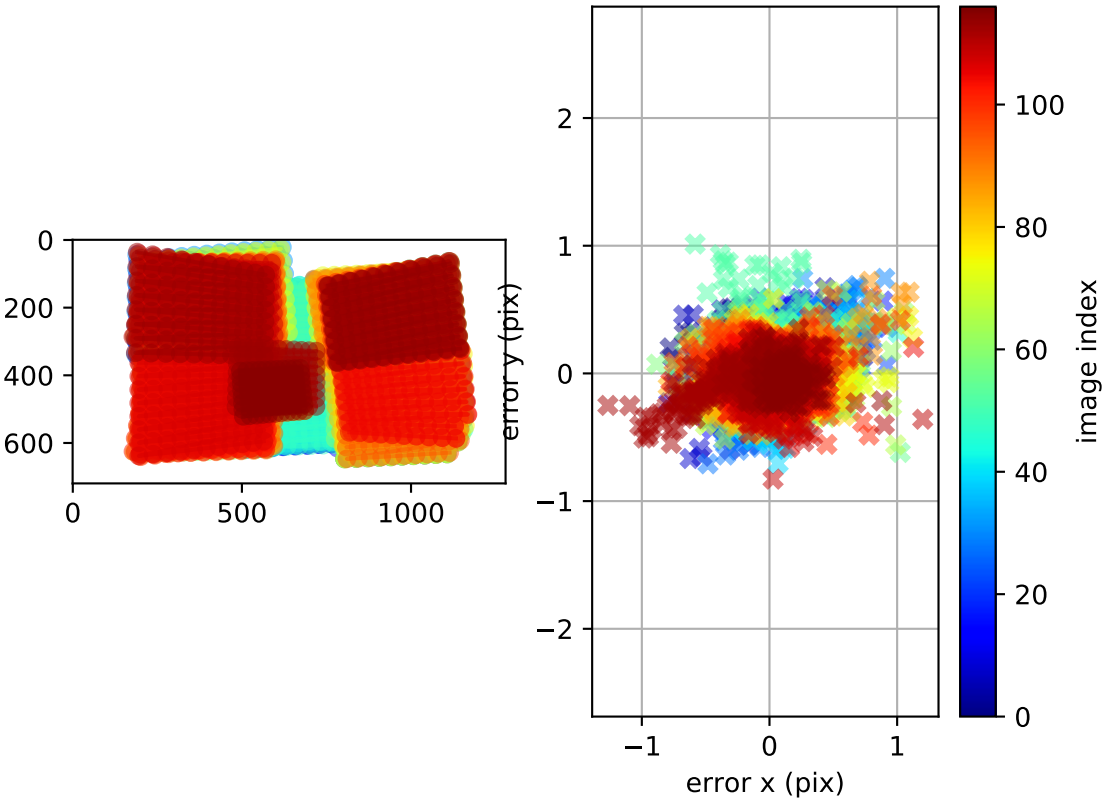


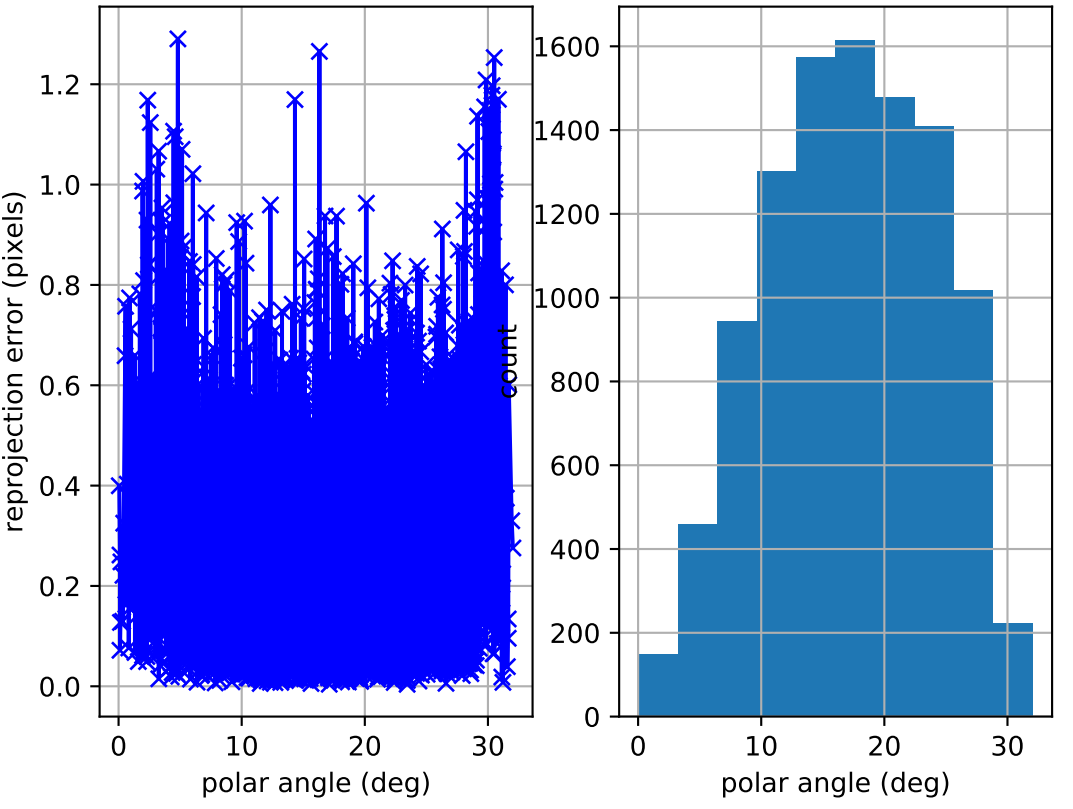

camera system
cam0
cam1
cam2
x
y
z
−0.075
−0.050
−0.025
0.000
0.025
0.050
0.075

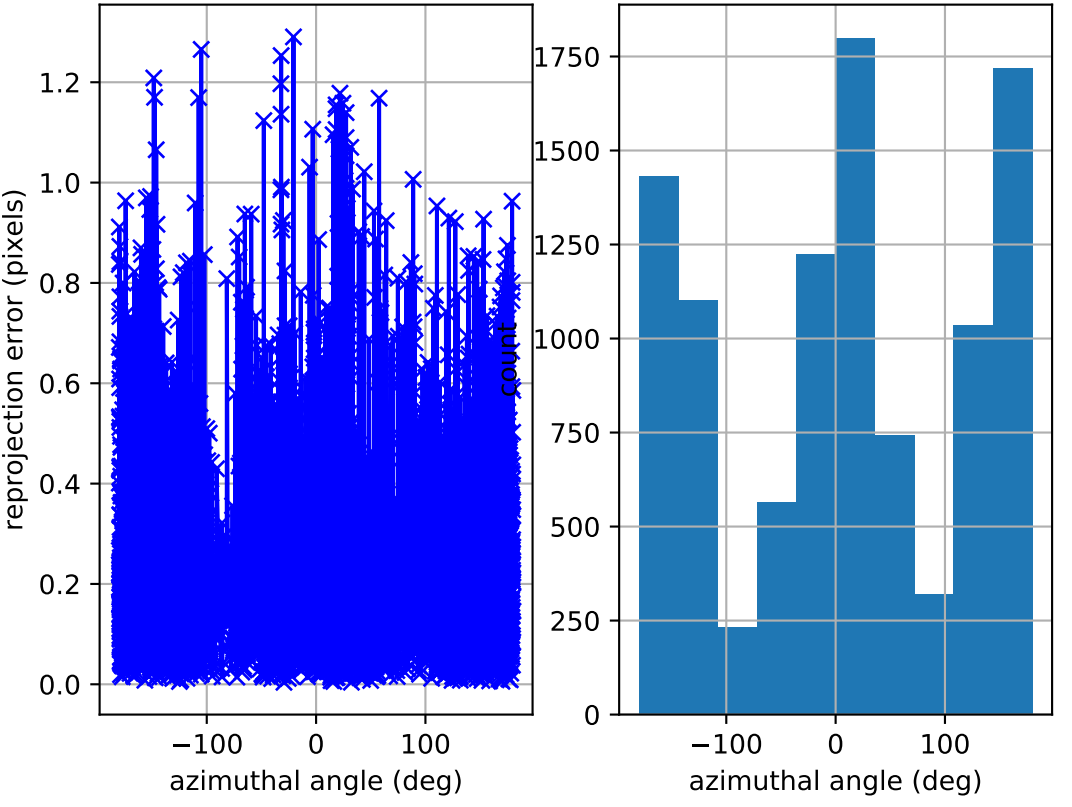

cam0: estimated poses
1.4
1.2
1.0
0.8
0.6
0.6
0.4
0.2
0.0
−0.2
−0.4
−0.6
−0.4
−0.2
0.0
0.2
0.4
0.6

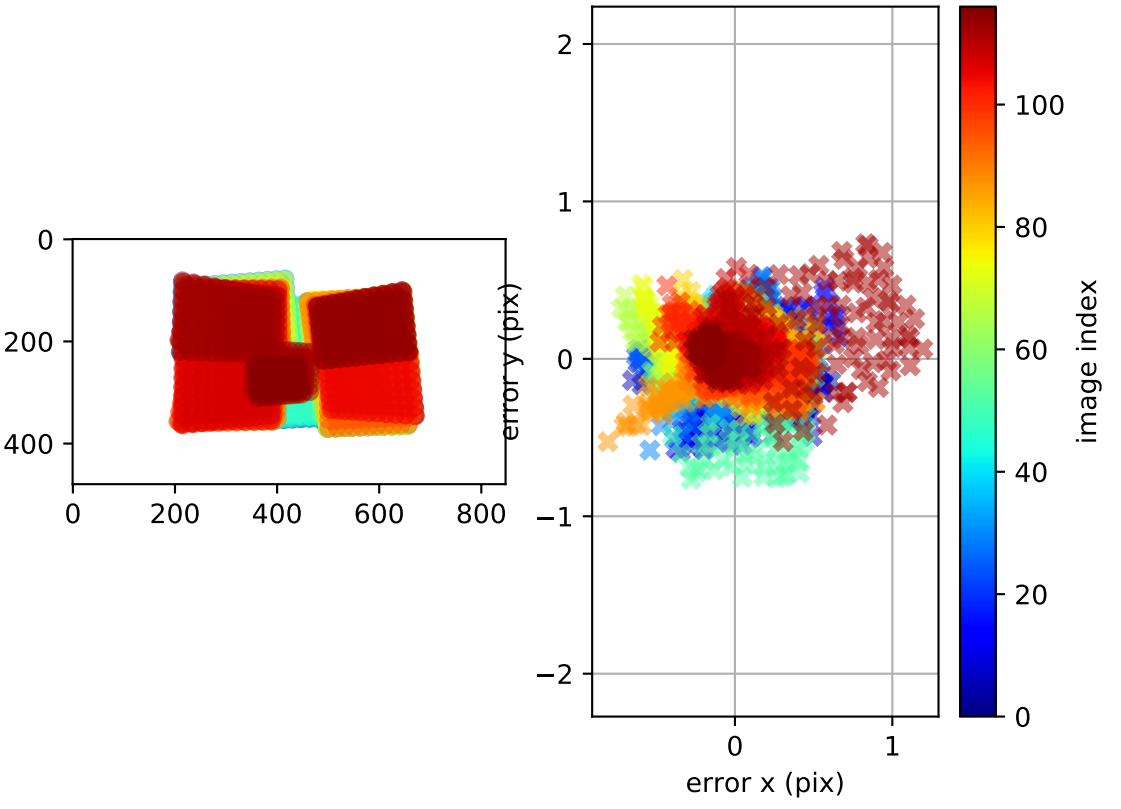

cam0: polar error
reprojection error (pixels)
polar angle (deg)
count
polar angle (deg)
0.0
0.2
0.4
0.6
0.8
1.0
1.2
0
200
400
600
800
1000
1200
1400
1600
0
10
20
30
0
10
20
30

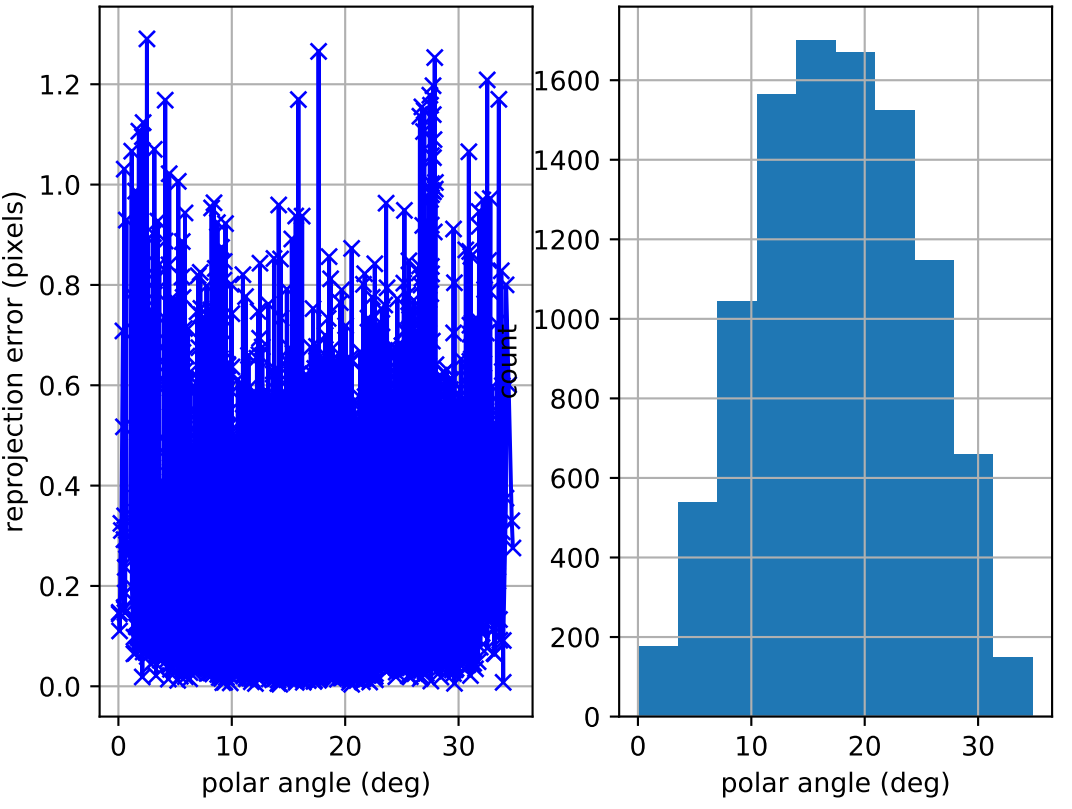

cam0: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)
0.0
0.2
0.4
0.6
0.8
1.0
1.2
−100
0
100
0
250
500
750
1000
1250
1500
1750
2000

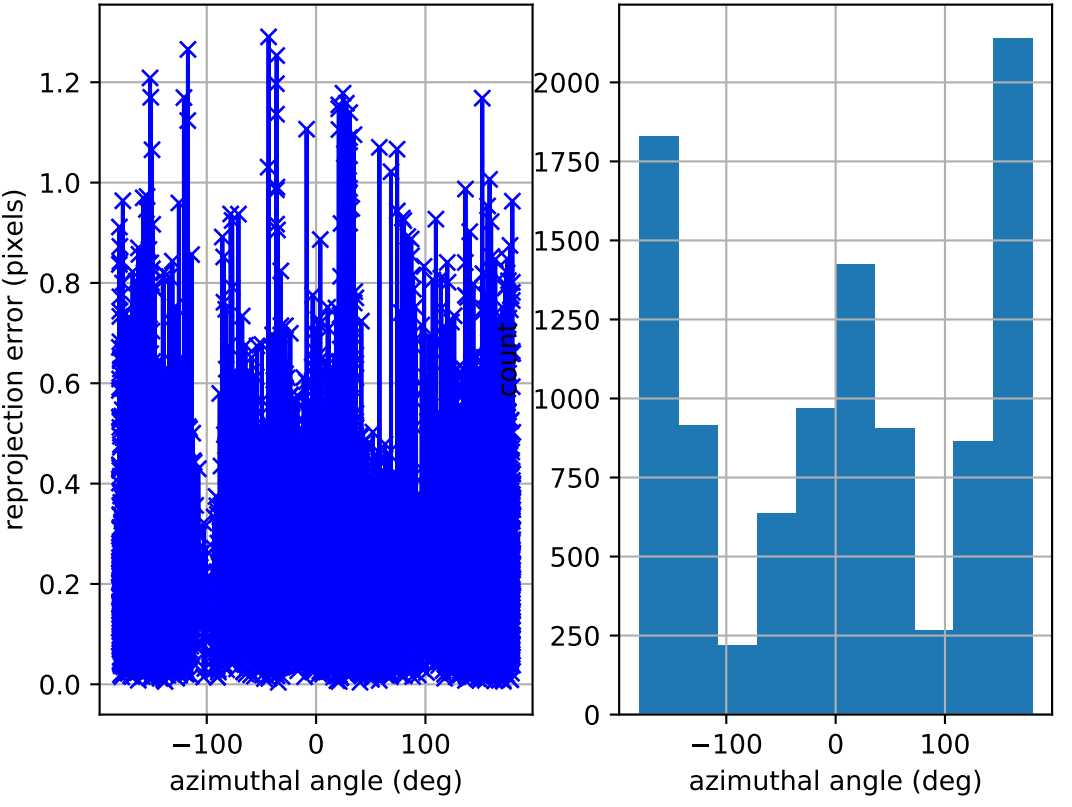

cam0: reprojection errors
0
200
400
600
0
500
1000
error y (pix)
2
1
0
−1
−2
−1
0
1
error x (pix)
100
80
60
40
20
0
image index

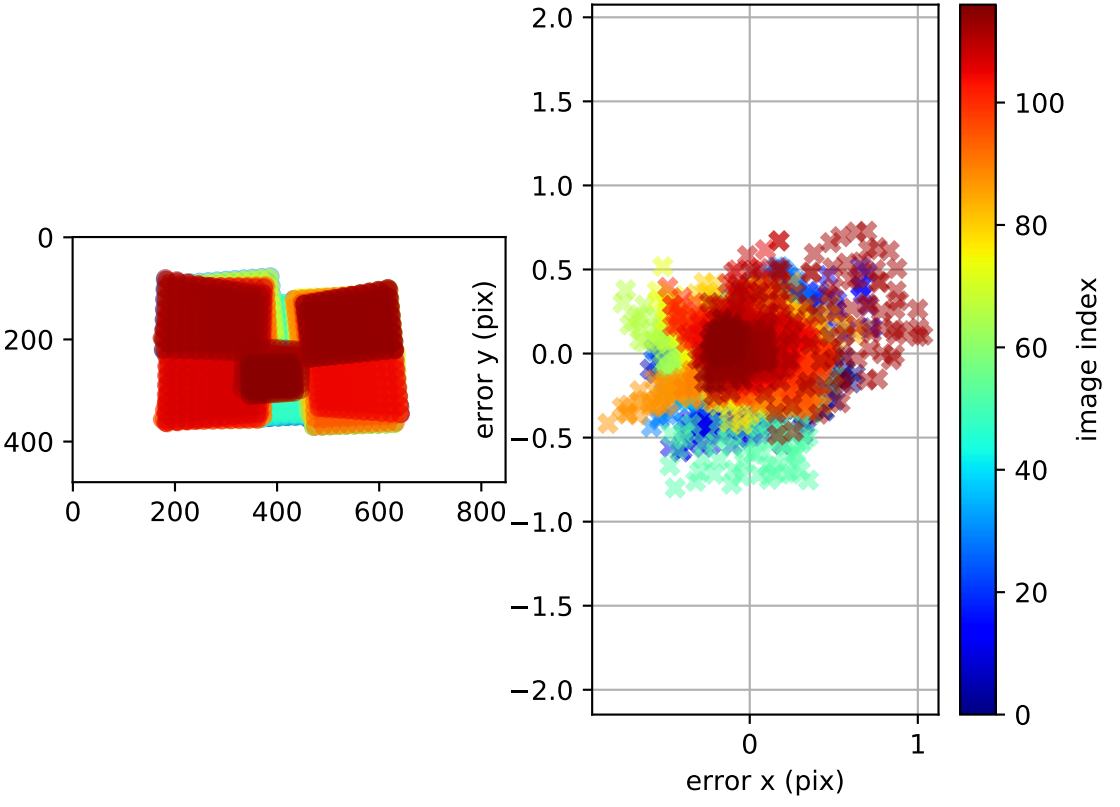

cam1: polar error
reprojection error (pixels)
polar angle (deg)
count
polar angle (deg)

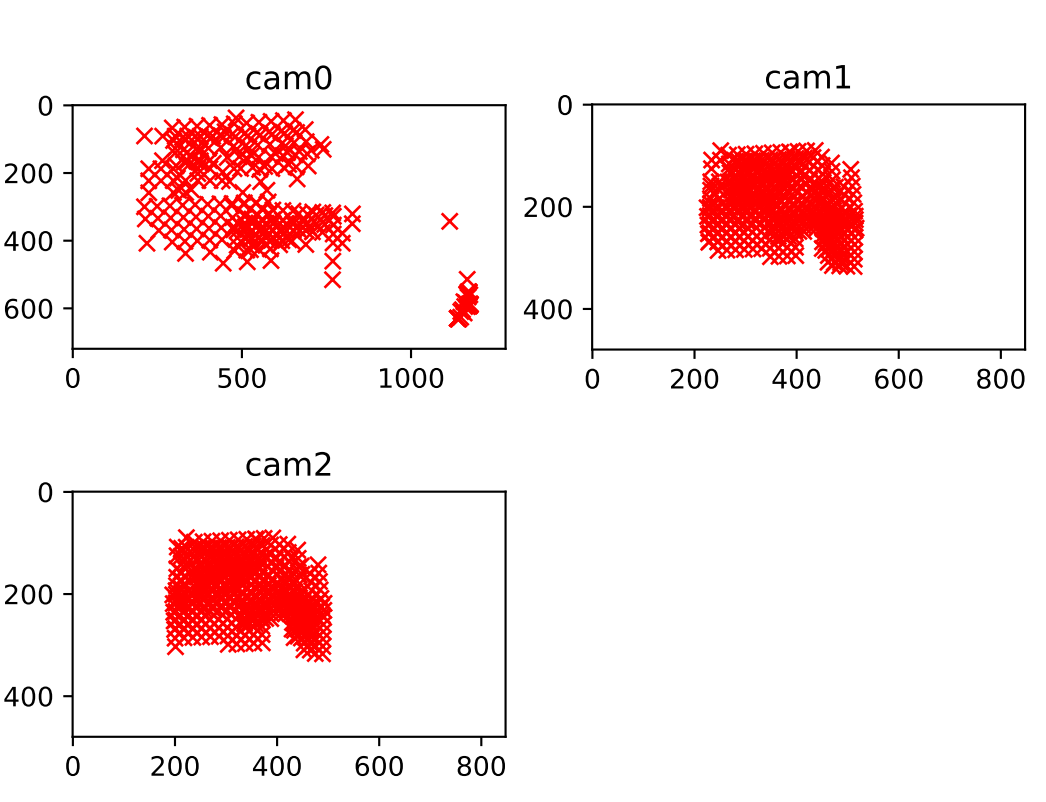

cam1: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)


cam1: reprojection errors
0
200
400
0
200
400
600
800
2
1
0
−1
−2
error y (pix)
0
1
error x (pix)
100
80
60
40
20
0
image index


cam2: polar error
reprojection error (pixels)
polar angle (deg)
count
polar angle (deg)
0.0
0.2
0.4
0.6
0.8
1.0
1.2
0
200
400
600
800
1000
1200
1400
1600
0
10
20
30
0
10
20
30


cam2: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)


cam2: reprojection errors
0
200
400
0
200
400
600
800
error y (pix)
2.0
1.5
1.0
0.5
0.0
−0.5
−1.0
−1.5
−2.0
0
1
error x (pix)
100
80
60
40
20
0
image index


Location of removed outlier corners
cam0
0
200
400
600
0
500
1000
cam1
0
200
400
0
200
400
600
800
cam2
0
200
400
0
200
400
600
800