Calibration results
====================
Camera-system parameters:
cam0 (/left_camera/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [-0.2160028   0.09168458 0.00026305 -0.00102638] +- [0.00106382 0.00159746 0.00013869 0.00010696]
projection: [856.67456501 855.9701916   648.37441175 531.70129936] +- [0.2991891   0.30720337 0.37099996
0.29747968]
reprojection error: [0.000030, -0.000019] +- [0.241635, 0.253784]

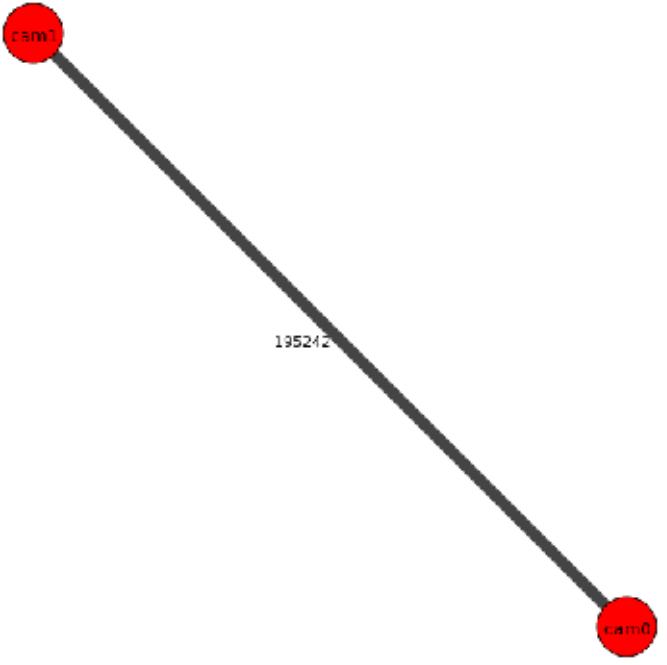
cam1 (/right_camera/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [-0.35297307 0.13932133 -0.00063475 0.00006446] +- [0.00115522 0.00155164 0.0001308   0.00013933]
projection: [697.43735991 697.24322251 630.6112434   501.82964716] +- [0.36300809 0.38617941 0.42765831
0.32066307]
reprojection error: [0.000012, -0.000017] +- [0.368704, 0.263087]

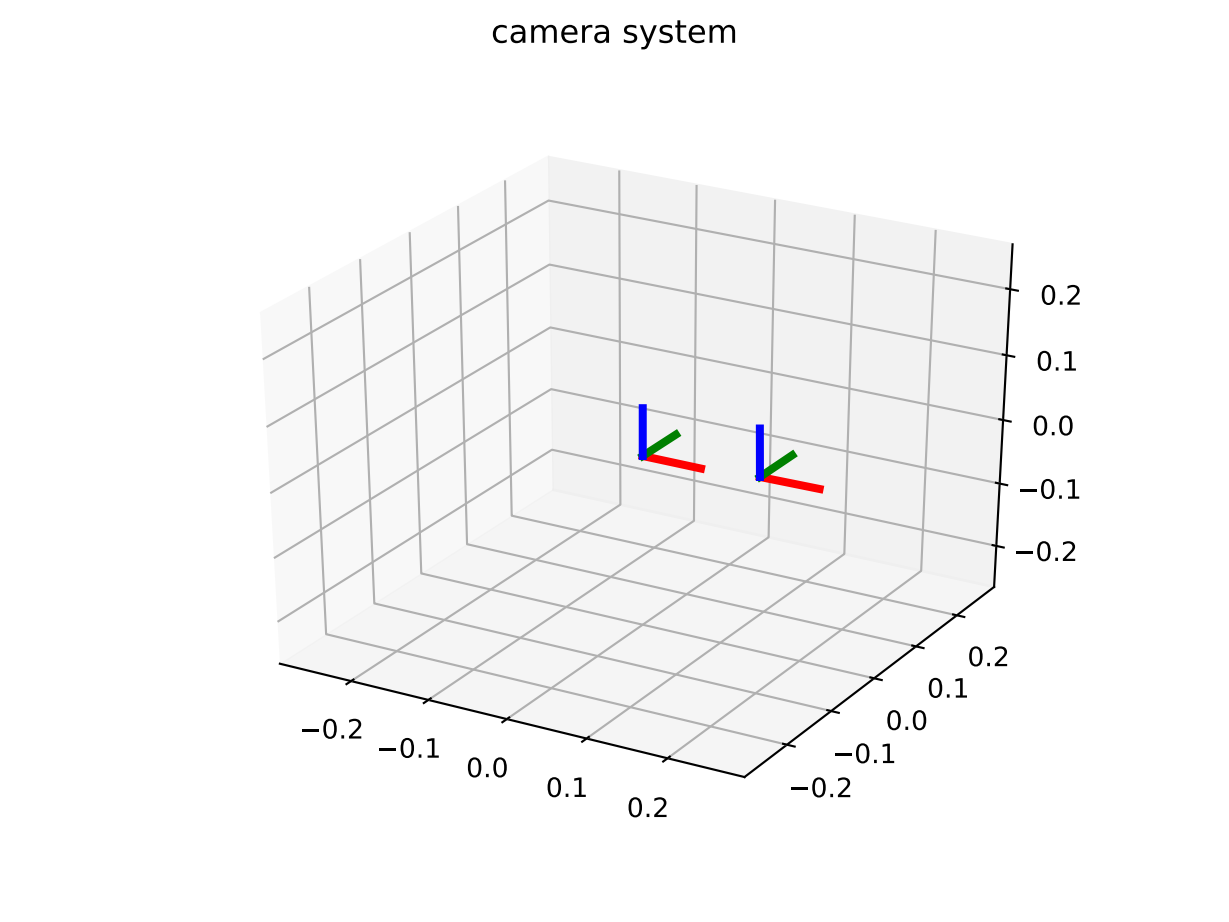
baseline T_1_0:
q: [-0.00051954 -0.008049   0.000432   0.99996738] +- [0.0008013   0.00100654 0.0001065]
t: [-0.14634816 -0.00011422 -0.00397526] +- [0.0000921   0.00008527 0.00038426]

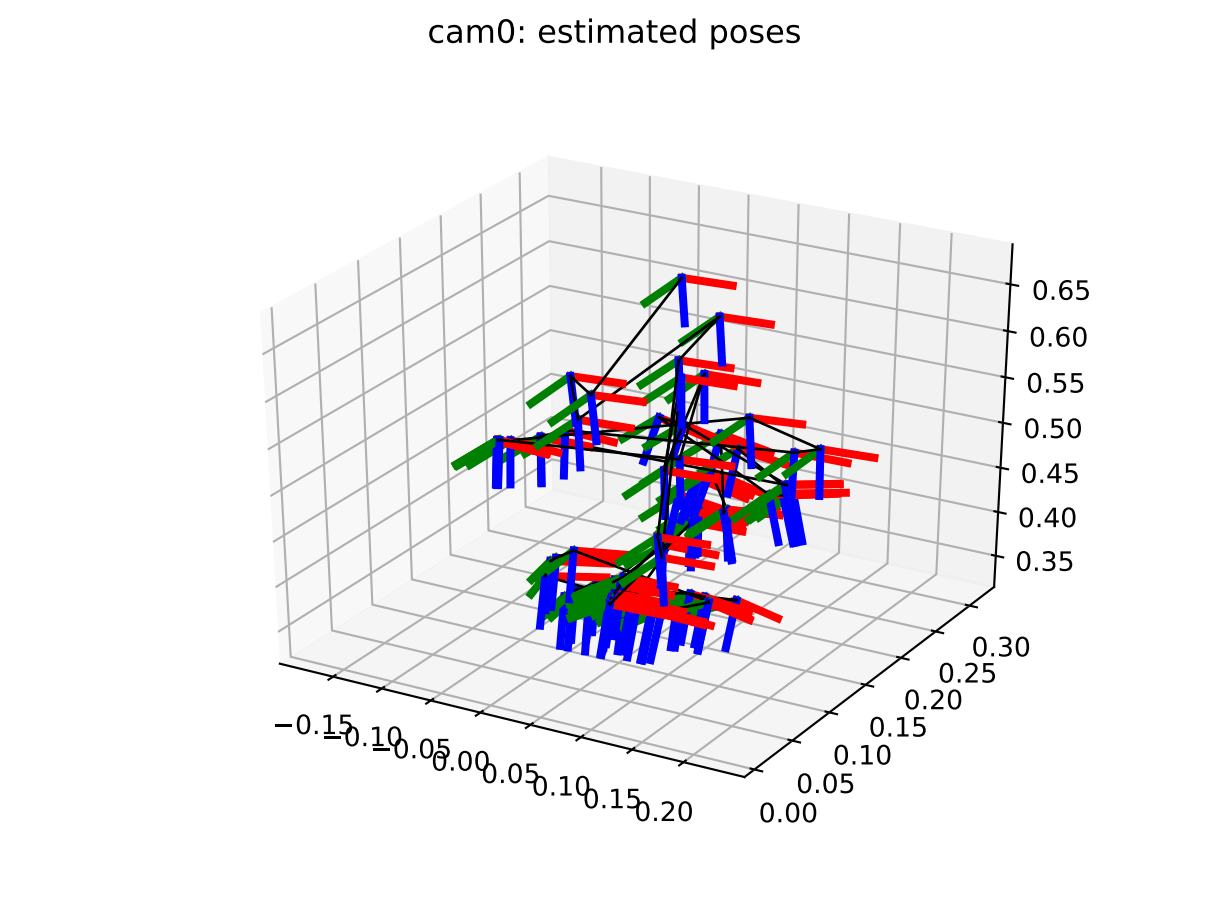
Target configuration
====================

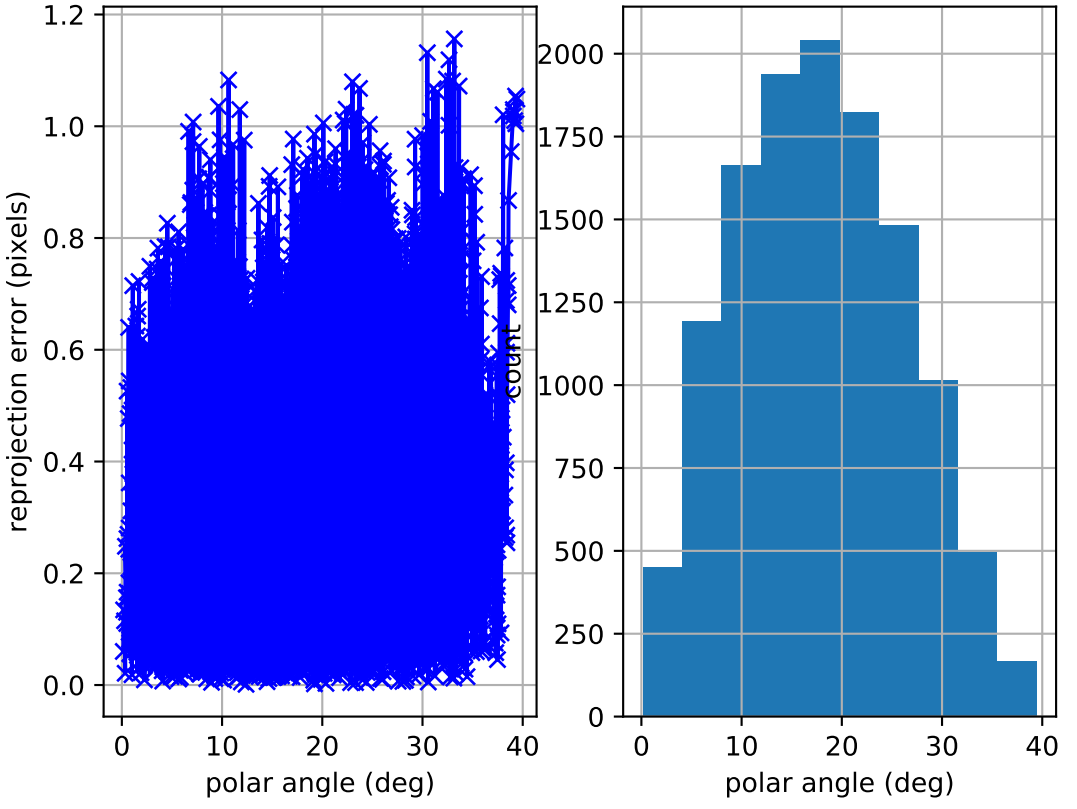
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.028 [m]
Spacing 0.0084 [m]

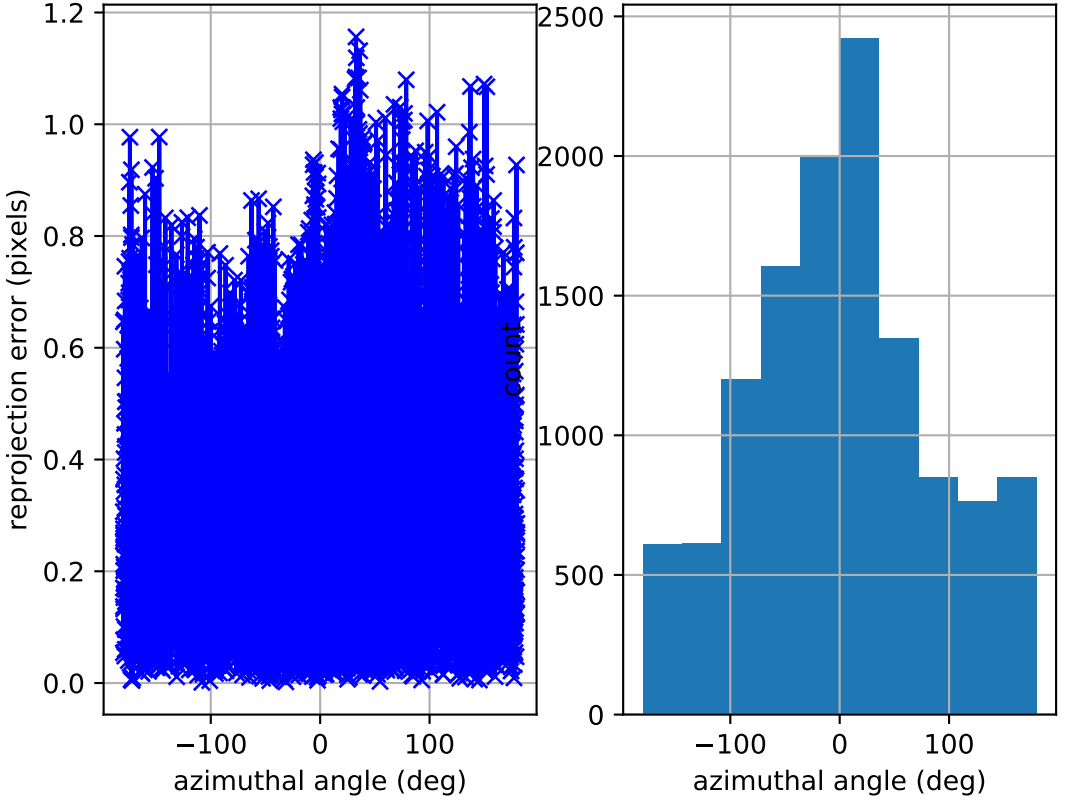
Inter-camera observations graph (edge weight=#mutual obs.)

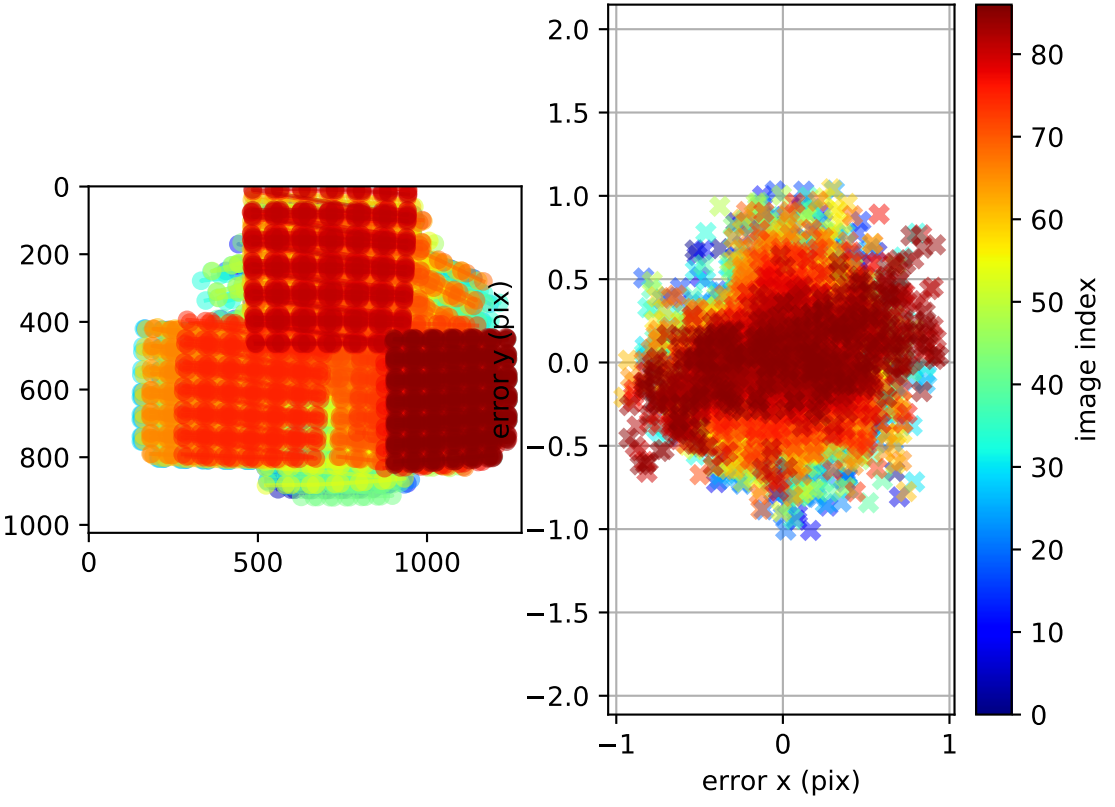


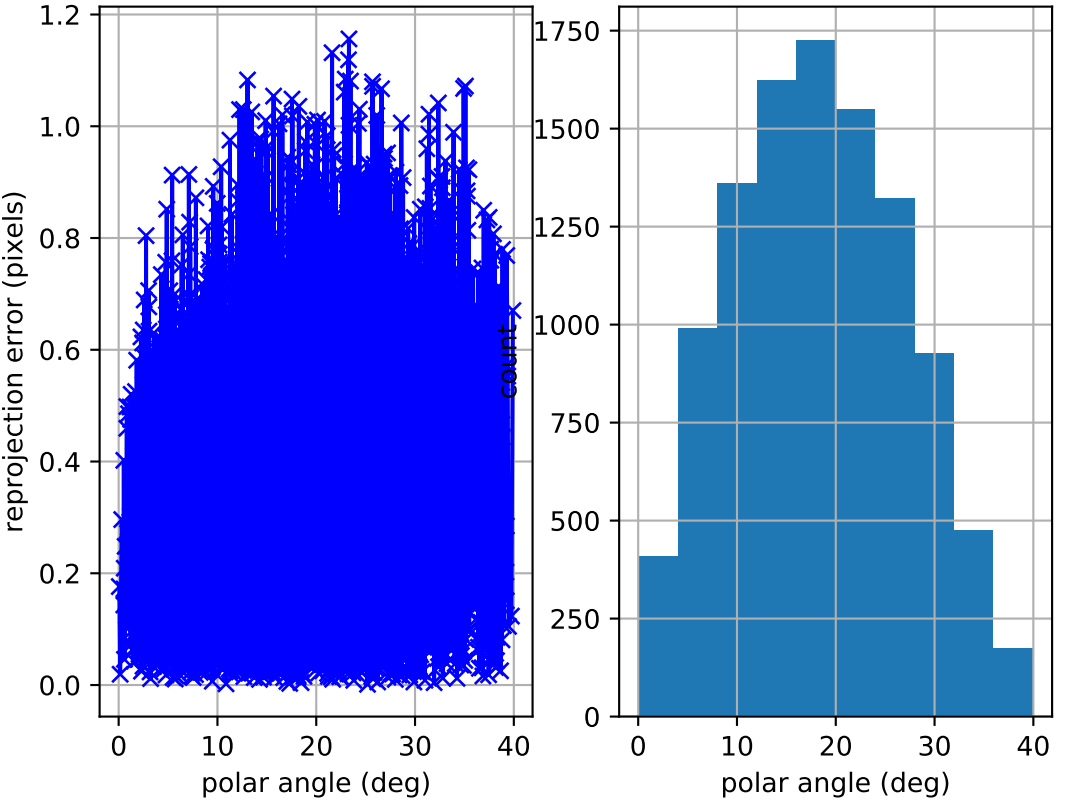

camera system
0.2
0.1
0.0
−0.1
−0.2
−0.2
−0.1
0.0
0.1
0.2
0.2
0.1
0.0
−0.1
−0.2

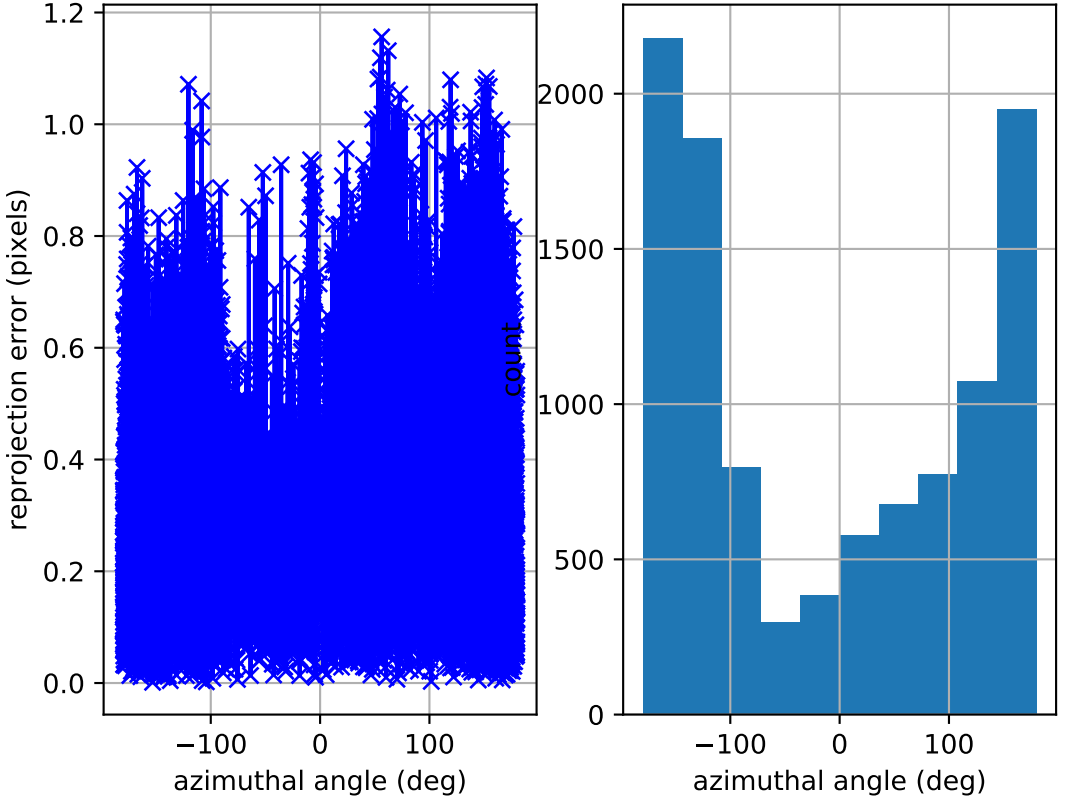

cam0: estimated poses
0.65
0.60
0.55
0.50
0.45
0.40
0.35
0.30
0.25
0.20
0.15
0.10
0.05
0.00
−0.15
−0.10
−0.05
0.00
0.05
0.10
0.15
0.20

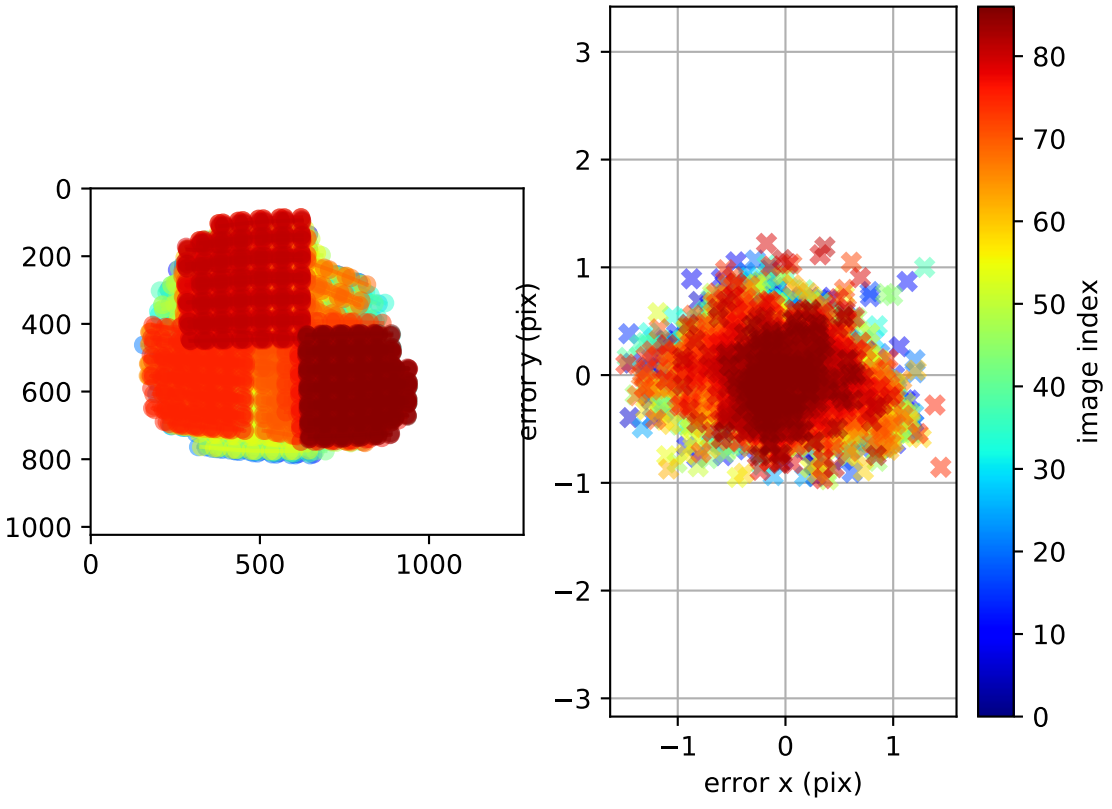

cam0: polar error
reprojection error (pixels)
1.2
1.0
0.8
0.6
0.4
0.2
0.0
0
10
20
30
40
polar angle (deg)
count
2000
1750
1500
1250
1000
750
500
250
0
0
10
20
30
40
polar angle (deg)

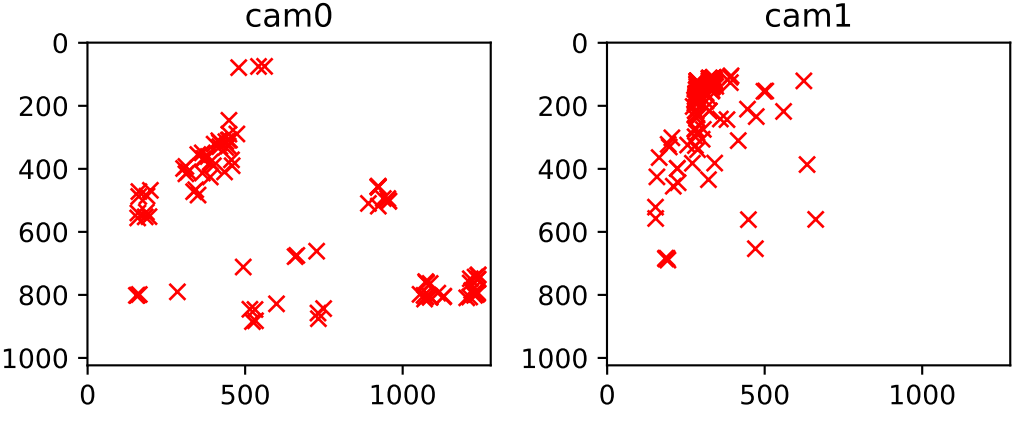

cam0: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)
0.0
0.2
0.4
0.6
0.8
1.0
1.2
−100
0
100
0
500
1000
1500
2000
2500


cam0: reprojection errors
0
200
400
600
800
1000
0
500
1000
error y (pix)
2.0
1.5
1.0
0.5
0.0
−0.5
−1.0
−1.5
−2.0
−1
0
1
error x (pix)
80
70
60
50
40
30
20
10
0
image index


cam1: 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
10
20
30
40
0
250
500
750
1000
1250
1500
1750


cam1: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)
1.2
1.0
0.8
0.6
0.4
0.2
0.0
−100
0
100
2000
1500
1000
500
0
−100
0
100


cam1: reprojection errors
0
200
400
600
800
1000
0
500
1000
3
2
1
0
−1
−2
−3
−1
0
1
error x (pix)
error y (pix)
80
70
60
50
40
30
20
10
0
image index


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