Calibration results
====================
Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [-0.00907279 0.05409554 -0.05186574 0.01078411] +- [0.00501221 0.01670433 0.02153104 0.00936707]
projection: [287.45363681 287.95458557 419.84649409 400.59213585] +- [0.13310066 0.13231173 0.28235563
0.15785158]
reprojection error: [-0.000001, 0.000000] +- [0.124886, 0.112992]

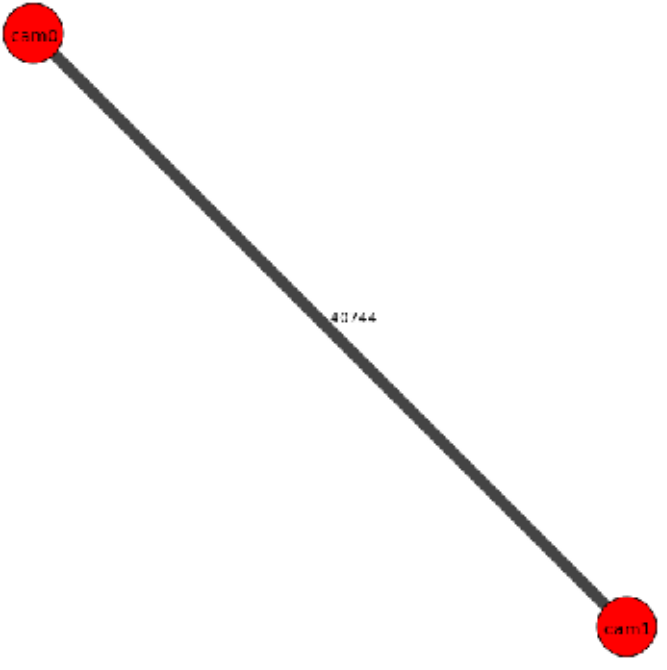
cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [-0.00945297 0.05803581 -0.06023631 0.01546072] +- [0.0057778   0.02087638 0.02926795 0.01392101]
projection: [288.00006461 288.61205511 420.44303314 386.90658219] +- [0.12877198 0.12948163 0.28629102
0.14105751]
reprojection error: [0.000001, -0.000000] +- [0.121374, 0.120056]

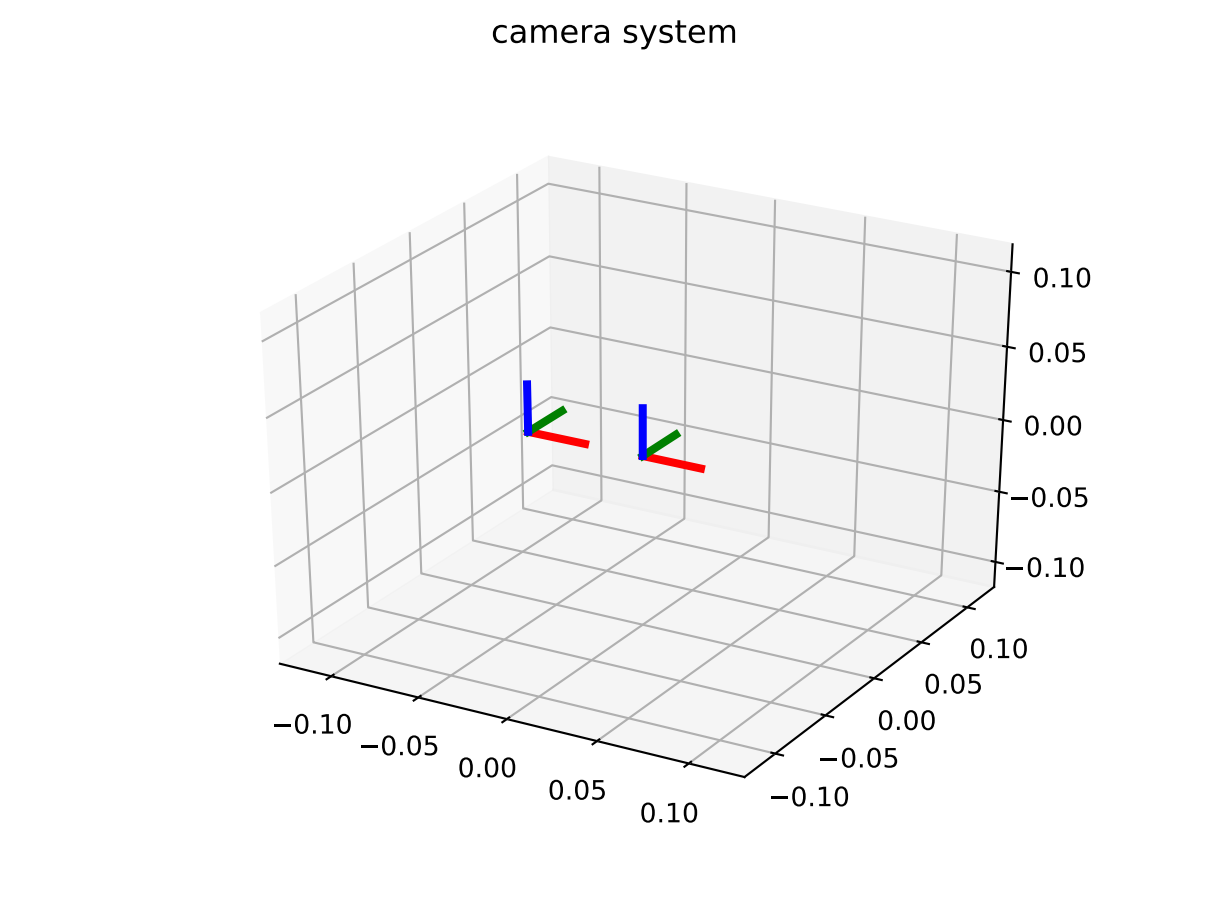
baseline T_1_0:
q: [0.00041296 -0.00207941 -0.00008972 0.99999775] +- [0.00094963 0.00088579 0.00012878]
t: [0.06478472 0.00007766 0.00003516] +- [0.000078   0.00008428 0.00019751]

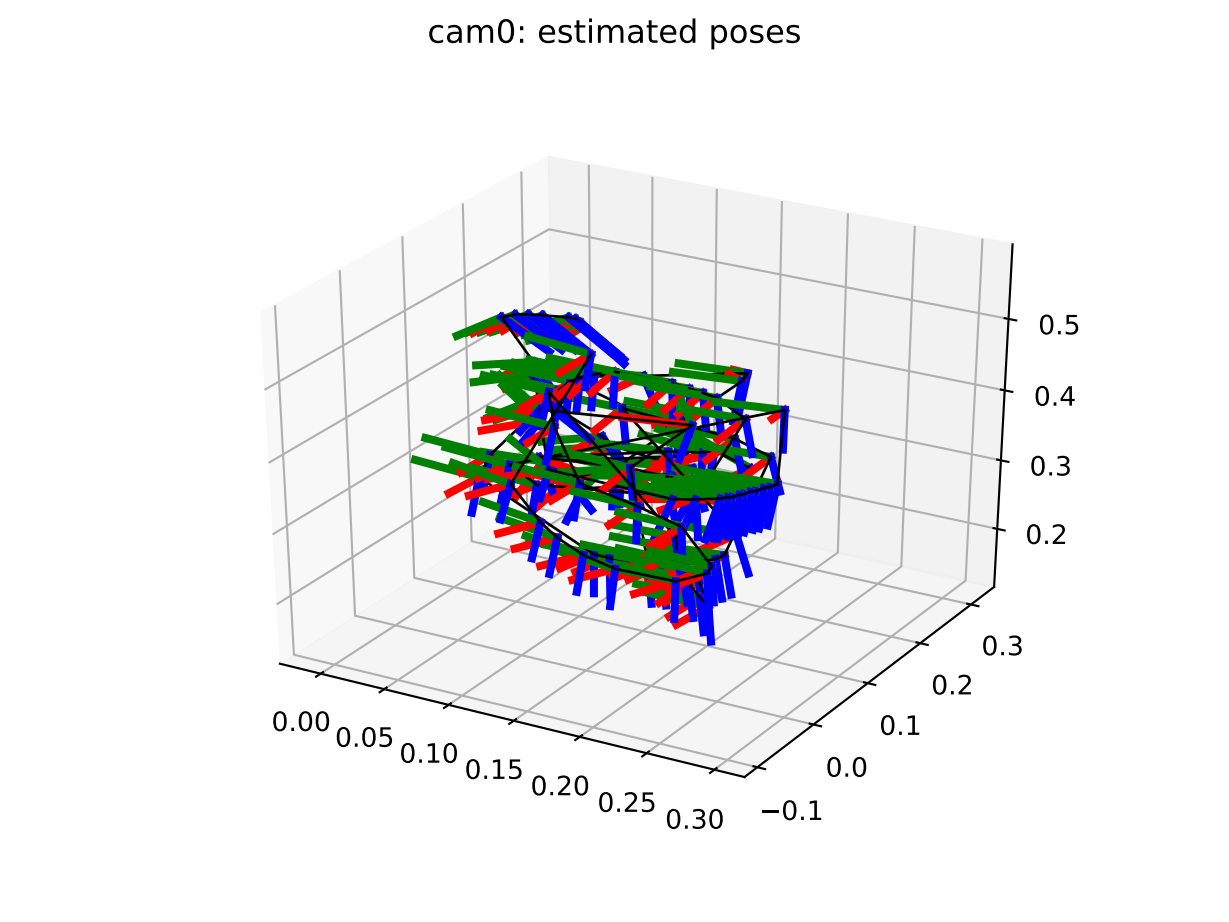
Target configuration
====================

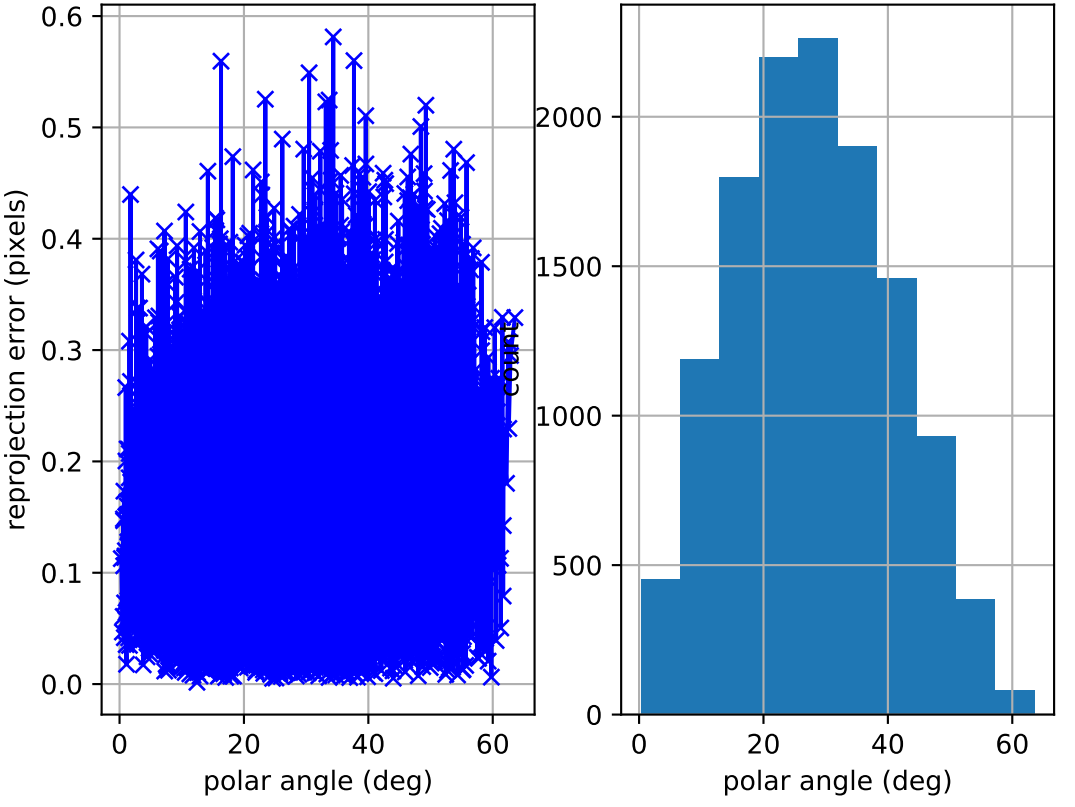
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0312 [m]
Spacing 0.00959999976 [m]

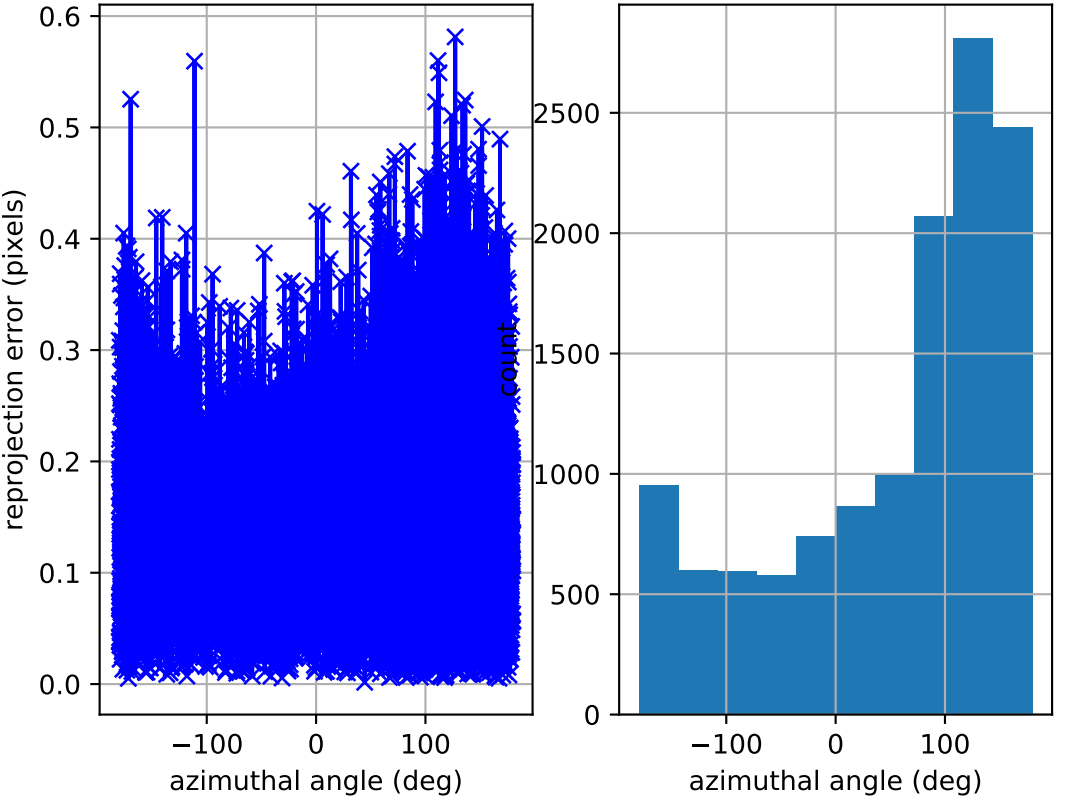
Inter-camera observations graph (edge weight=#mutual obs.)

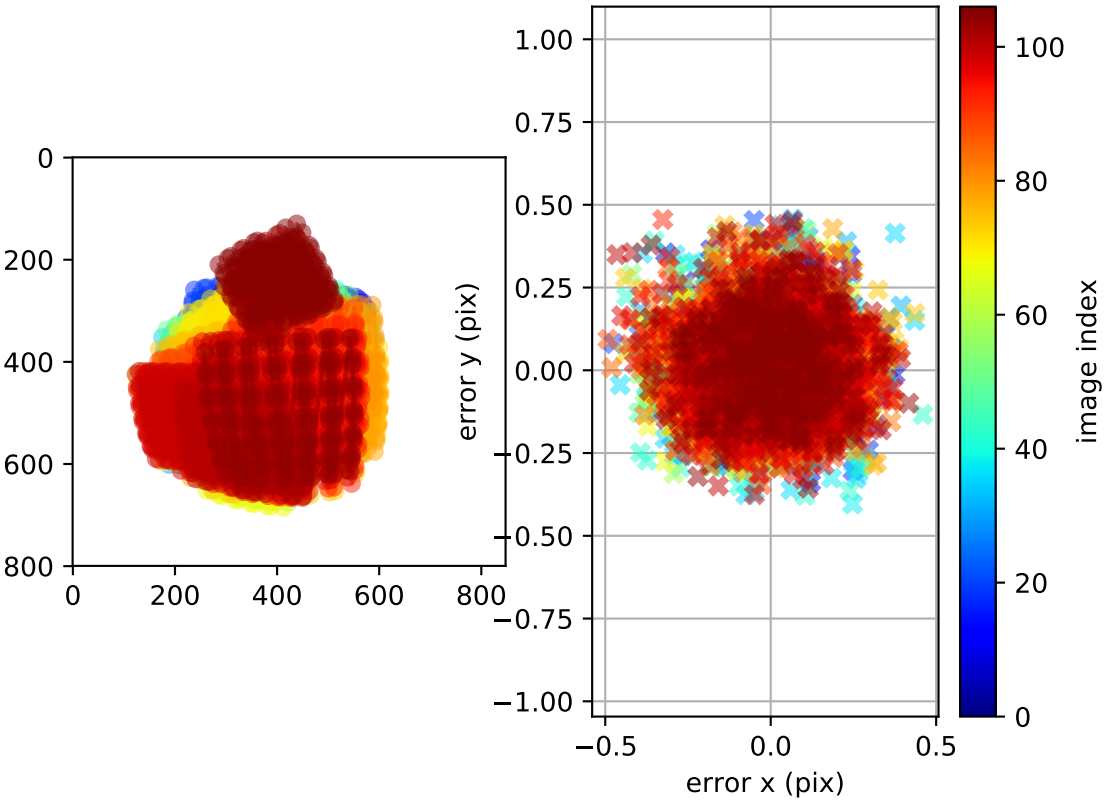


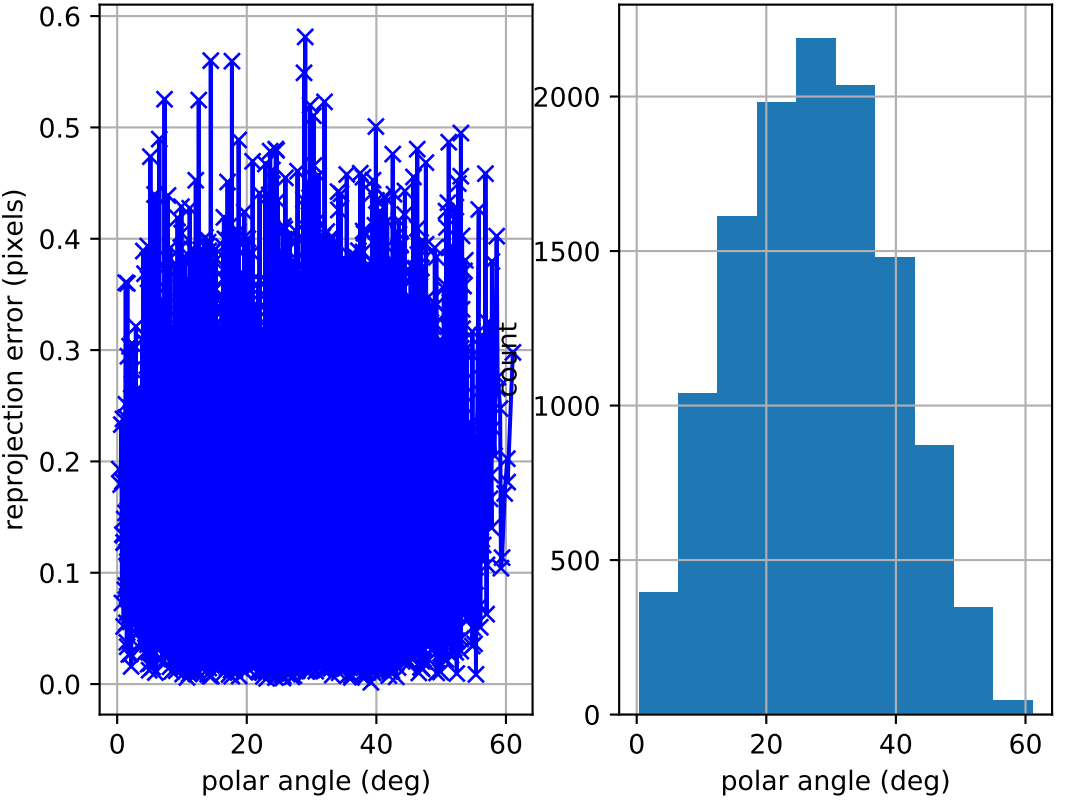

camera system
0.10
0.05
0.00
−0.05
−0.10
−0.10
−0.05
0.00
0.05
0.10
0.10
0.05
0.00
−0.05
−0.10

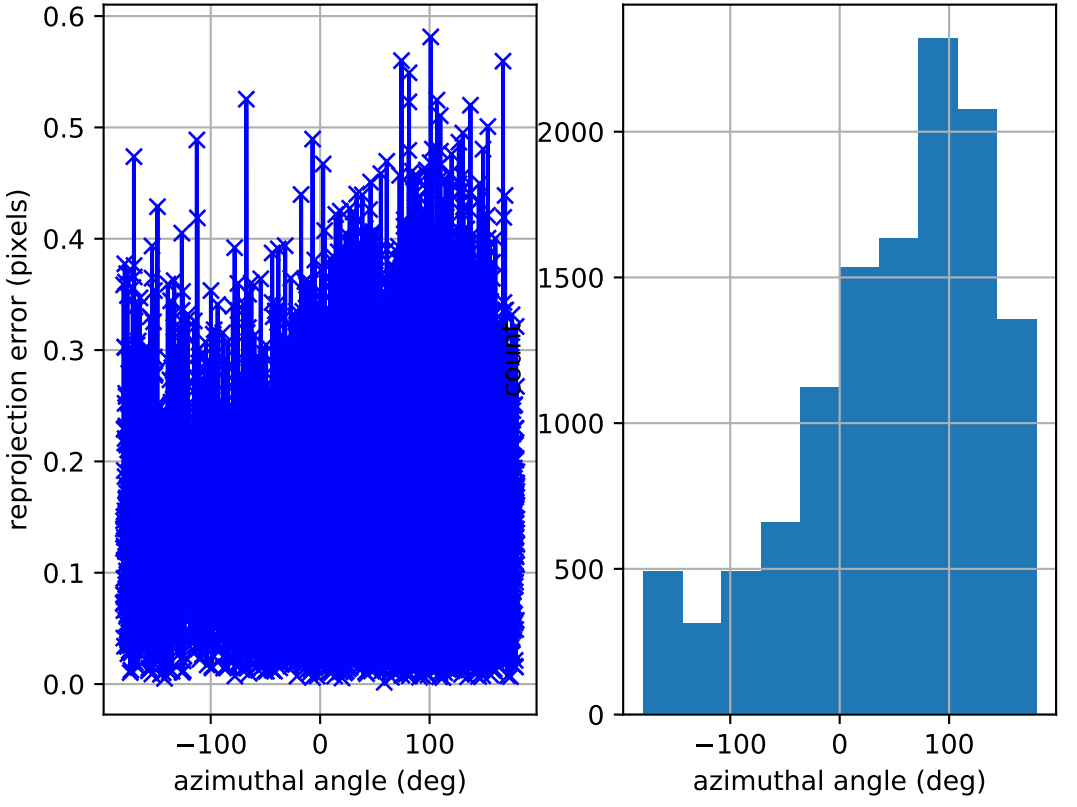

cam0: estimated poses
0.5
0.4
0.3
0.2
0.3
0.2
0.1
0.0
−0.1
0.00
0.05
0.10
0.15
0.20
0.25
0.30

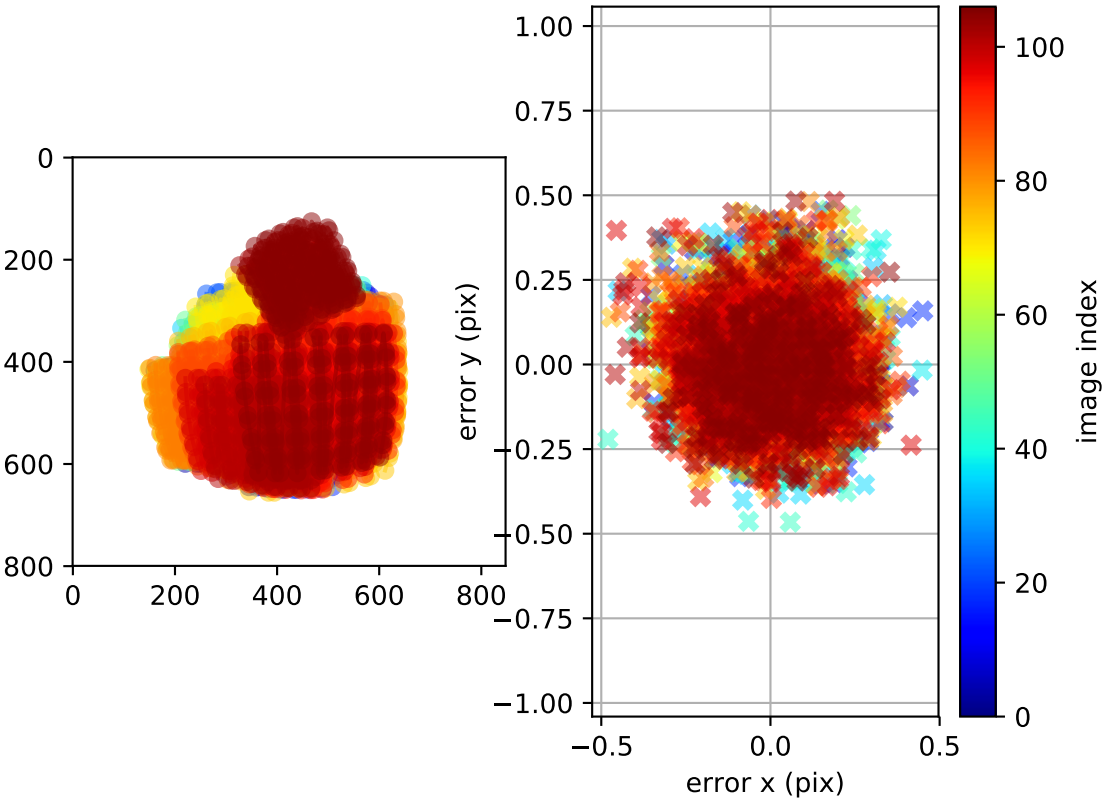

cam0: polar error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
0.6
0
20
40
60
polar angle (deg)
count
0
500
1000
1500
2000
0
20
40
60
polar angle (deg)

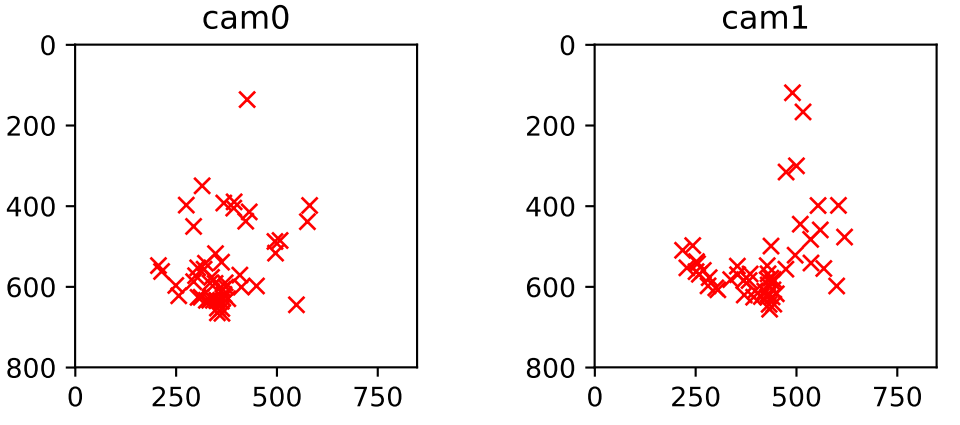

cam0: azimuthal error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
0.6
−100
0
100
azimuthal angle (deg)
count
0
500
1000
1500
2000
2500
−100
0
100
azimuthal angle (deg)


cam0: reprojection errors
0
200
400
600
800
error y (pix)
1.00
0.75
0.50
0.25
0.00
−0.25
−0.50
−0.75
−1.00
−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
20
40
60
polar angle (deg)
count
0
500
1000
1500
2000
0
20
40
60
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
−100
0
100
azimuthal angle (deg)


cam1: reprojection errors
0
200
400
600
800
0
200
400
600
800
error y (pix)
1.00
0.75
0.50
0.25
0.00
−0.25
−0.50
−0.75
−1.00
−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
200
400
600
800
0
250
500
750