Calibration results
====================
Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.FovDistortedPinholeCameraGeometry'>
distortion: [0.94996929] +- [0.0030341]
projection: [271.42948986 271.60004304 315.58293611 200.08317741] +- [0.50498169 0.50820433 1.19289954 0.9116196]
reprojection error: [0.000005, -0.000001] +- [0.097961, 0.079451]

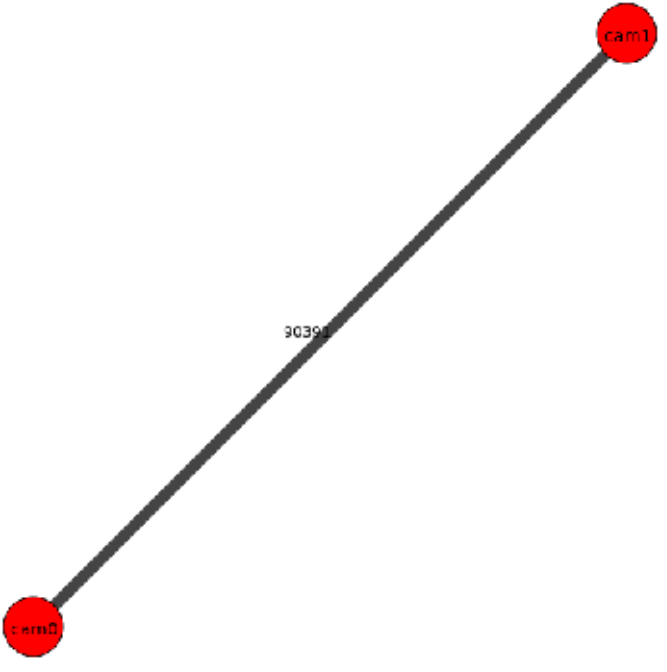
cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.FovDistortedPinholeCameraGeometry'>
distortion: [0.94872247] +- [0.00340942]
projection: [271.59987421 271.77828254 315.52219059 200.919281] +- [0.52166006 0.52612459 1.14466856 1.10832473]
reprojection error: [-0.000005, 0.000006] +- [0.087490, 0.087555]

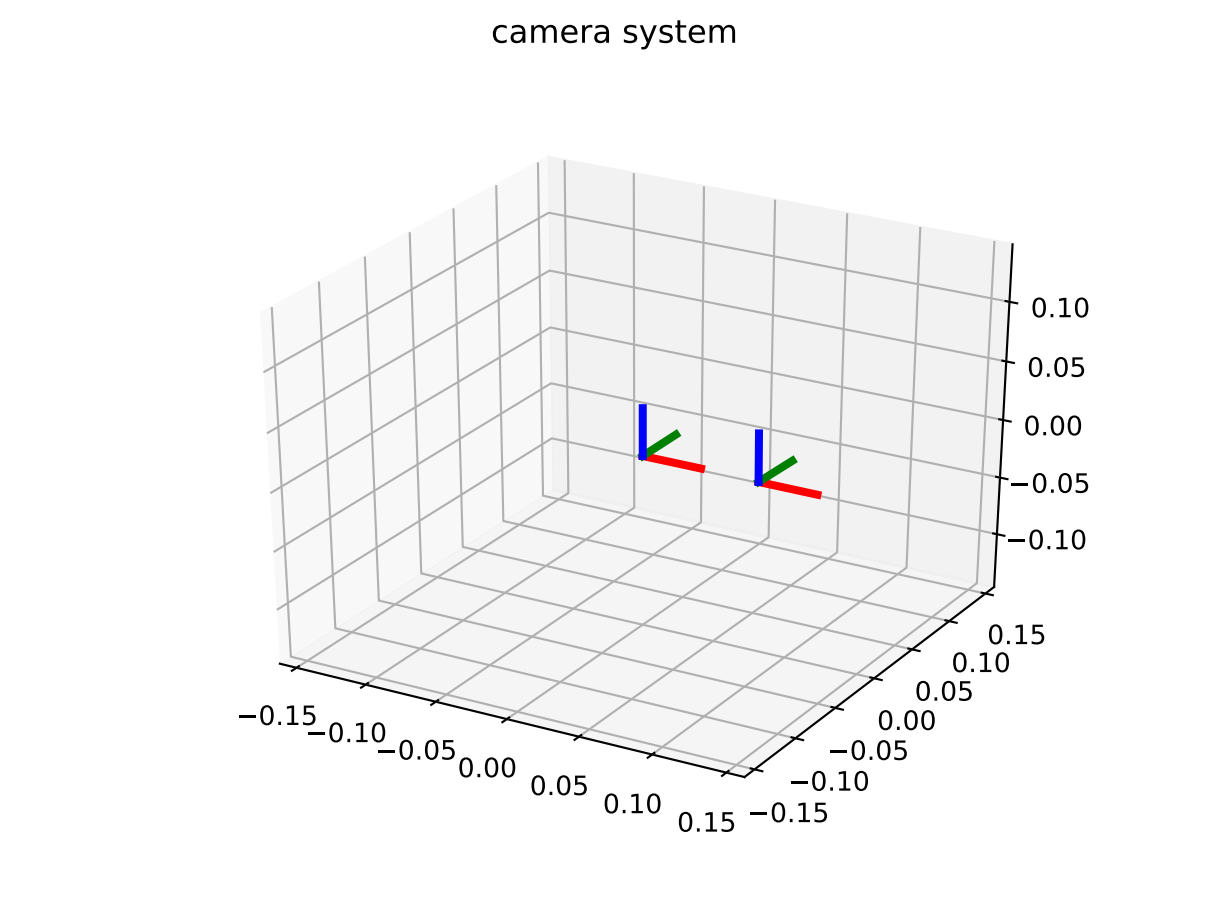
baseline T_1_0:
q: [-0.00455465 -0.00616642 -0.01193971 0.99989933] +- [0.00409727 0.00433723 0.00039906]
t: [-0.08084983 -0.00037284 0.00092114] +- [0.00046401 0.00039231 0.00197967]

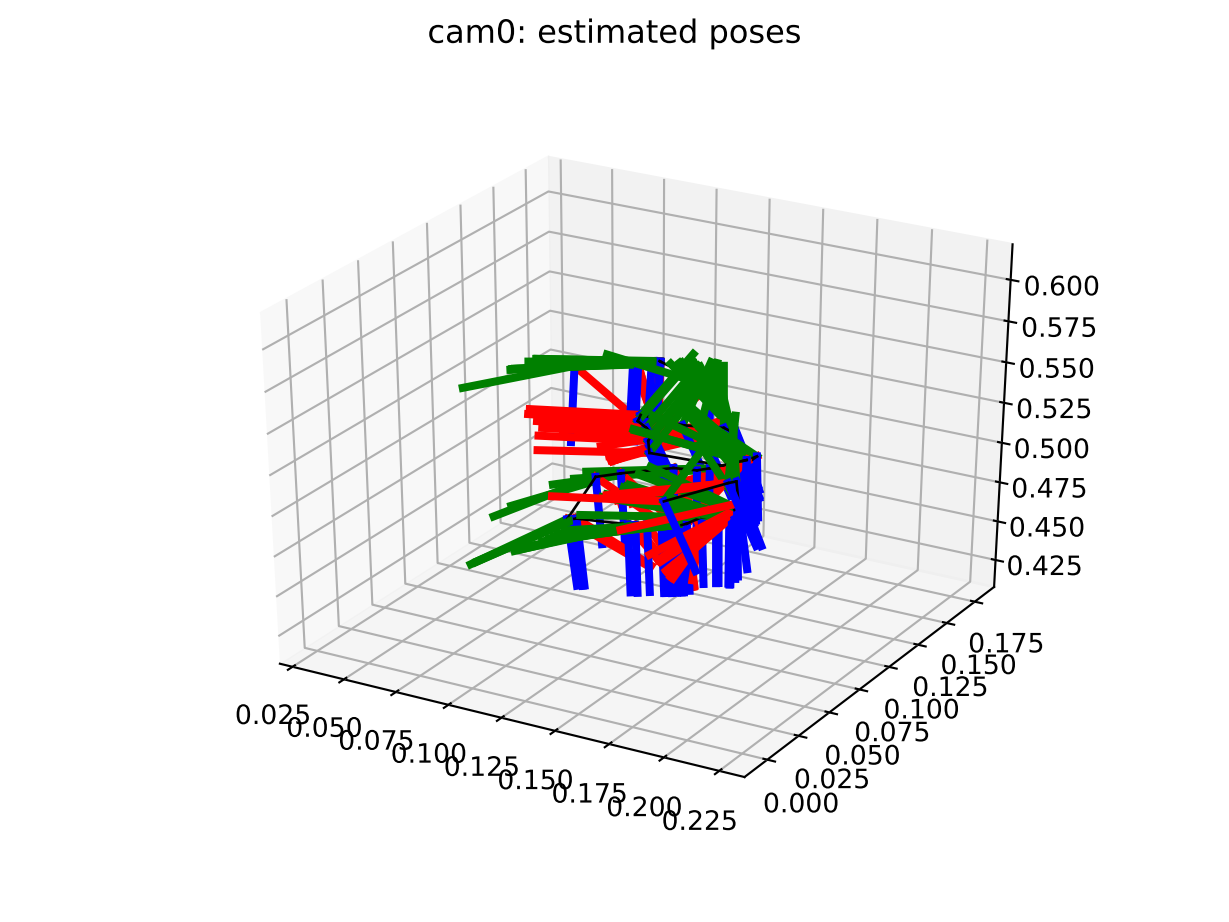
Target configuration
====================

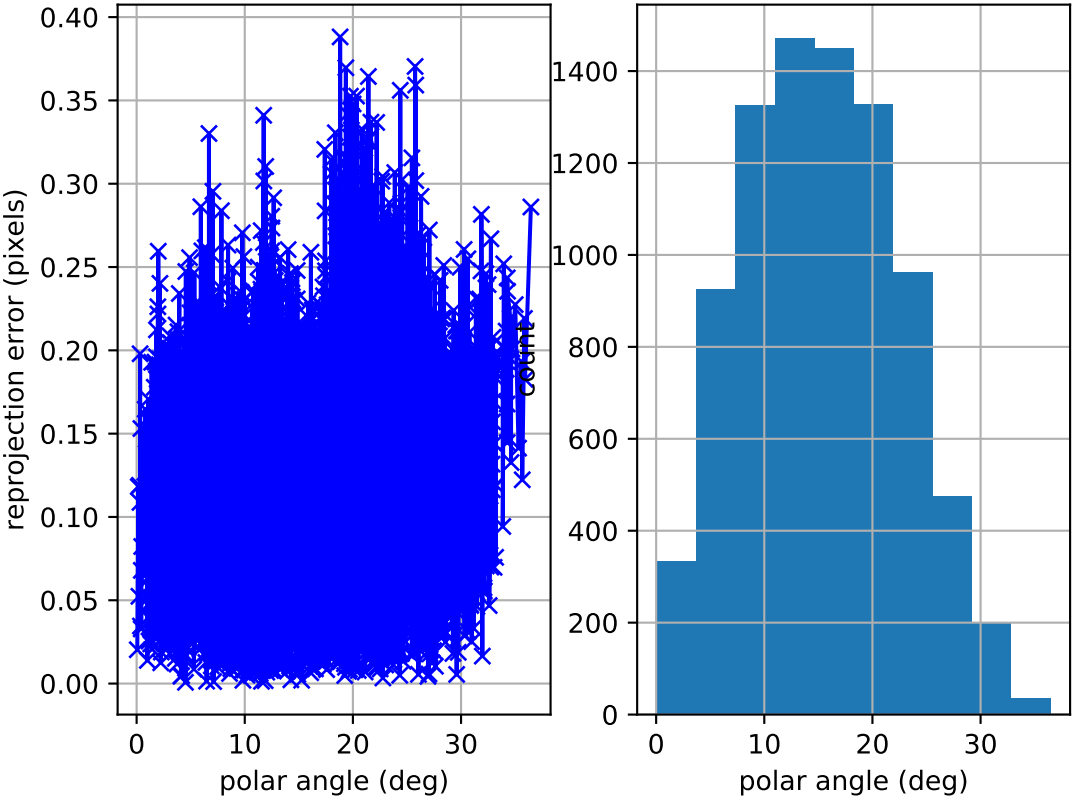
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0312 [m]
Spacing 0.00959999976 [m]

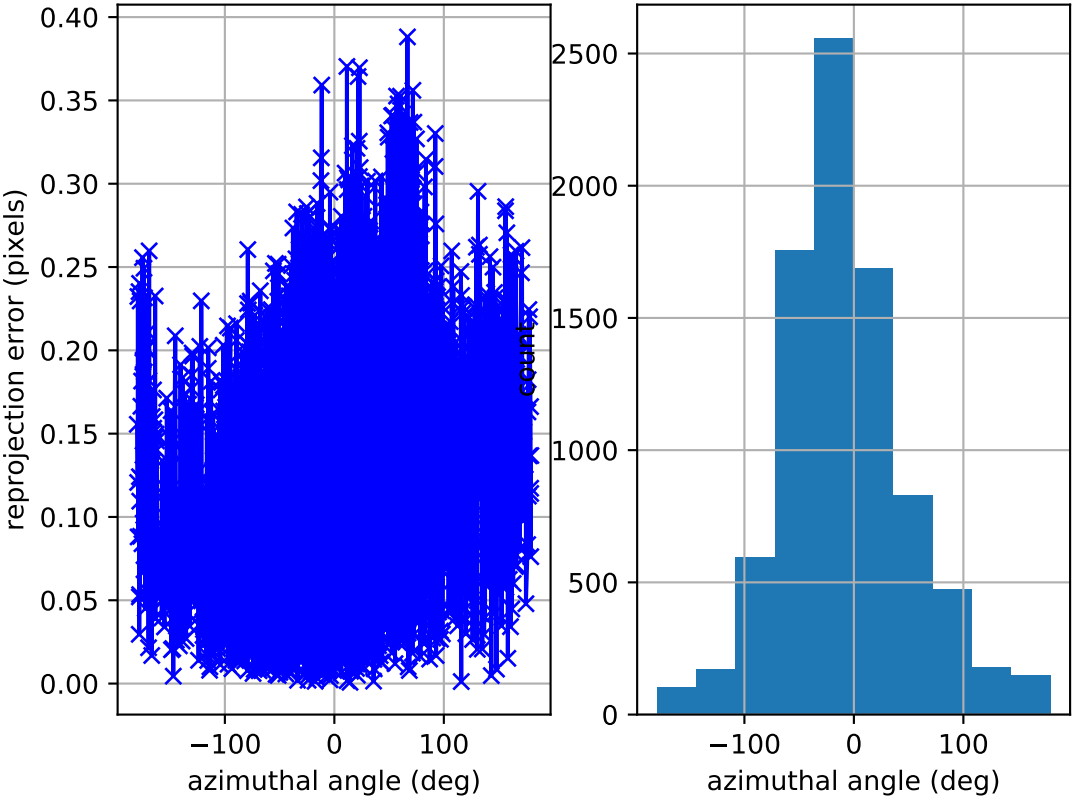
Inter-camera observations graph (edge weight=#mutual obs.)

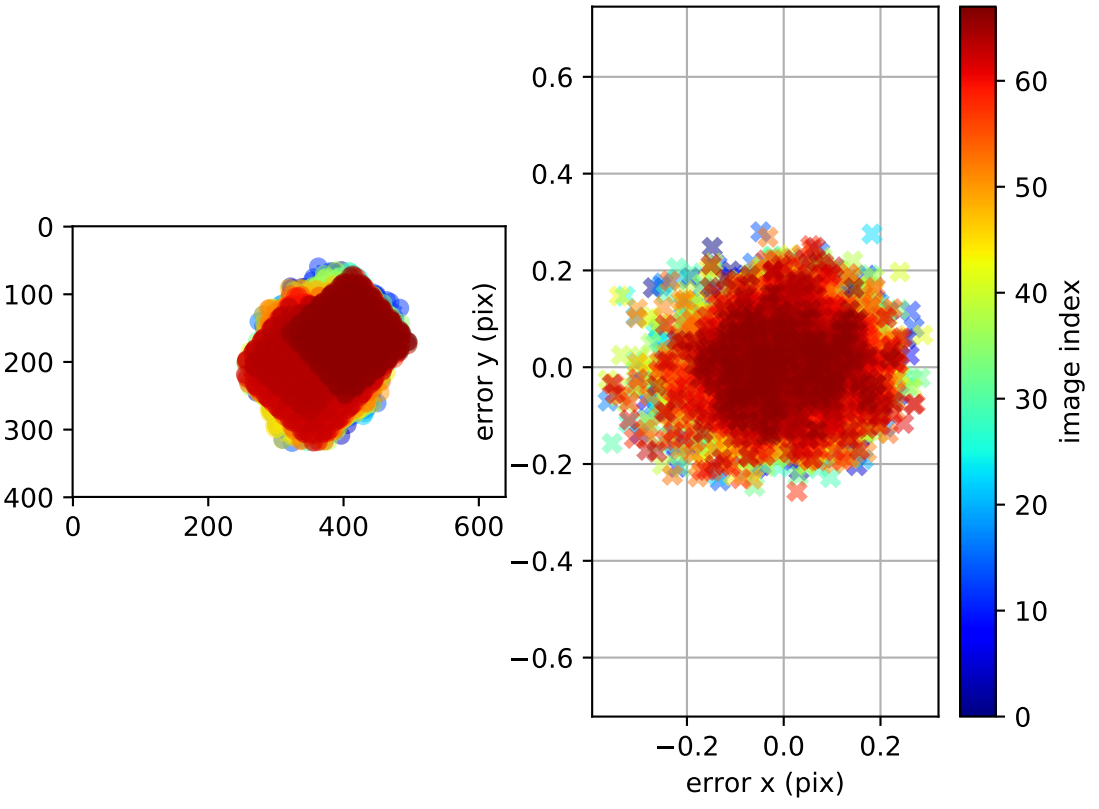


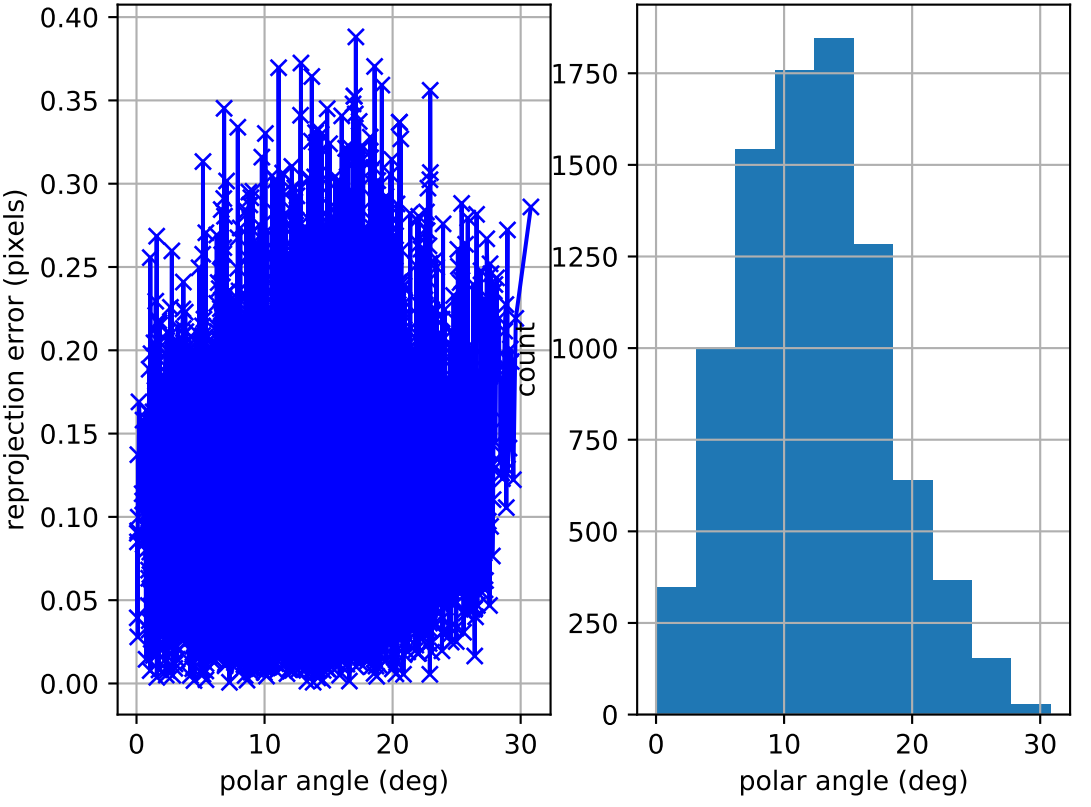

camera system
0.10
0.05
0.00
−0.05
−0.10
0.15
0.10
0.05
0.00
−0.05
−0.10
−0.15
−0.15
−0.10
−0.05
0.00
0.05
0.10
0.15

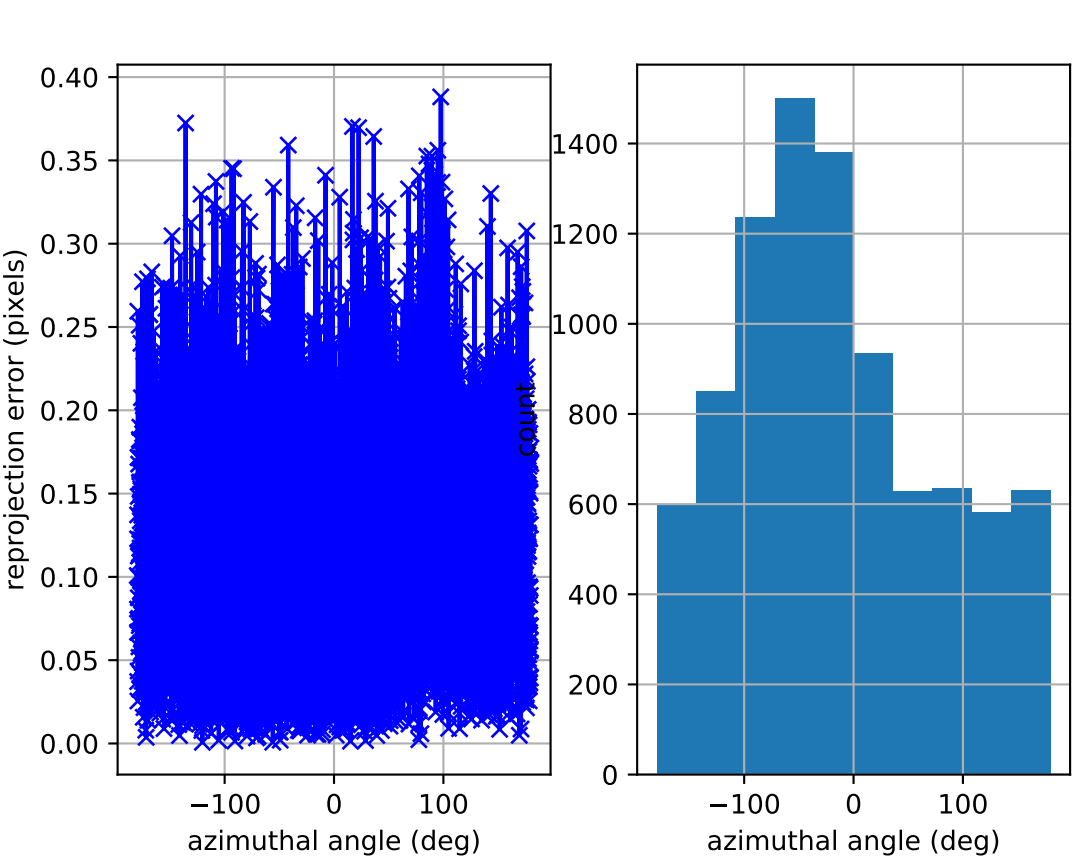

cam0: estimated poses
0.600
0.575
0.550
0.525
0.500
0.475
0.450
0.425
0.175
0.150
0.125
0.100
0.075
0.050
0.025
0.000
0.025
0.050
0.075
0.100
0.125
0.150
0.175
0.200
0.225

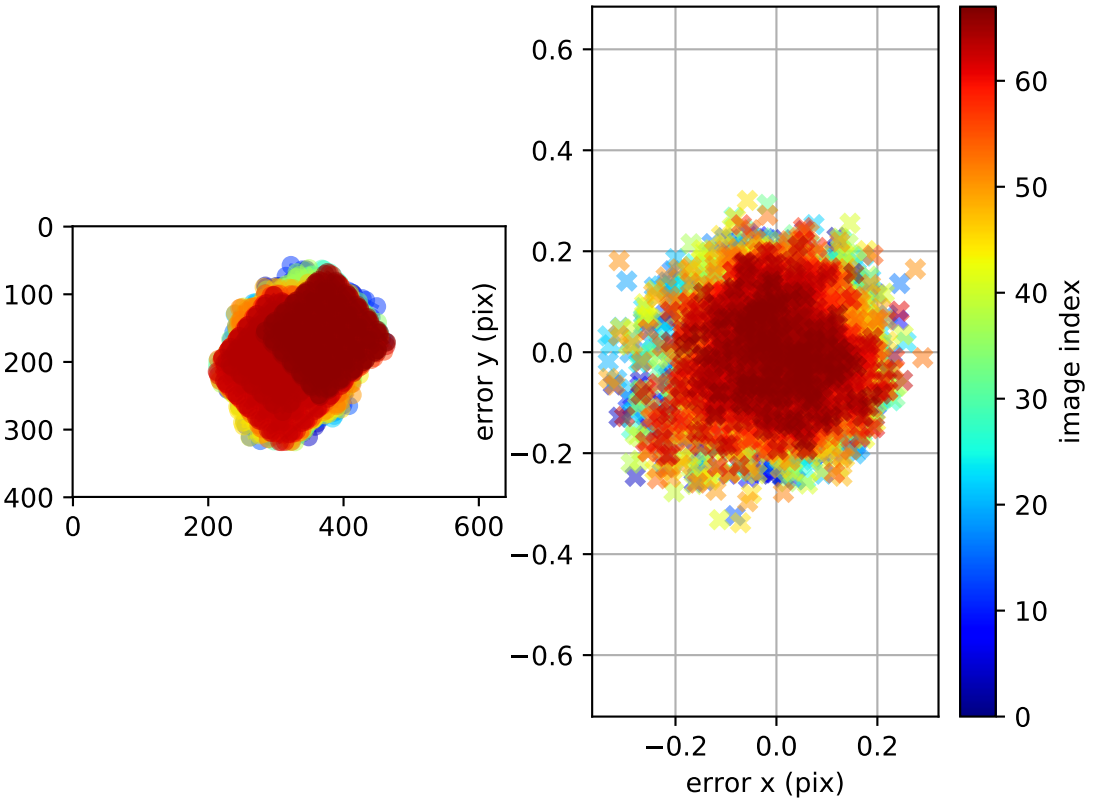

cam0: polar error
reprojection error (pixels)
0.40
0.35
0.30
0.25
0.20
0.15
0.10
0.05
0.00
0
10
20
30
polar angle (deg)
count
1400
1200
1000
800
600
400
200
0
0
10
20
30
polar angle (deg)

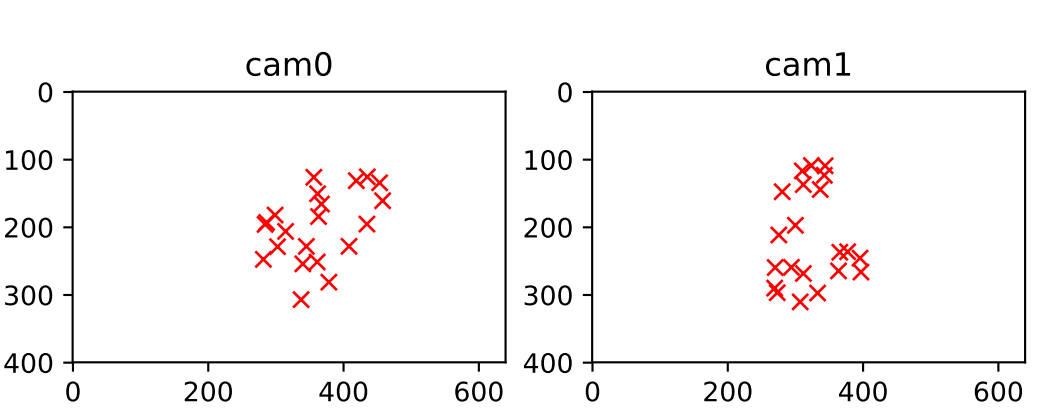

cam0: azimuthal error
reprojection error (pixels)
0.40
0.35
0.30
0.25
0.20
0.15
0.10
0.05
0.00
−100
0
100
azimuthal angle (deg)
count
2500
2000
1500
1000
500
0
−100
0
100
azimuthal angle (deg)


cam0: reprojection errors
0
100
200
300
400
0
200
400
600
error y (pix)
0.6
0.4
0.2
0.0
−0.2
−0.4
−0.6
−0.2
0.0
0.2
error x (pix)
0
10
20
30
40
50
60
image index


cam1: polar error
reprojection error (pixels)
0.40
0.35
0.30
0.25
0.20
0.15
0.10
0.05
0.00
0
10
20
30
polar angle (deg)
count
1750
1500
1250
1000
750
500
250
0
0
10
20
30
polar angle (deg)


cam1: azimuthal error
reprojection error (pixels)
0.40
0.35
0.30
0.25
0.20
0.15
0.10
0.05
0.00
−100
0
100
azimuthal angle (deg)
count
1400
1200
1000
800
600
400
200
0
−100
0
100
azimuthal angle (deg)


cam1: reprojection errors
0
100
200
300
400
0
200
400
600
error y (pix)
0.6
0.4
0.2
0.0
−0.2
−0.4
−0.6
−0.2
0.0
0.2
error x (pix)
60
50
40
30
20
10
0
image index


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