Calibration results
====================
Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.ExtendedUnifiedCameraGeometry'>
distortion: [] +- []
projection: [0.5799121   1.18332519 288.91187705 289.67598319 316.3553068
200.91392182] +- [0.01081681 0.02766514 0.18168026 0.1818277   0.26815571 0.24539706]
reprojection error: [-0.000002, 0.000003] +- [0.125372, 0.115567]

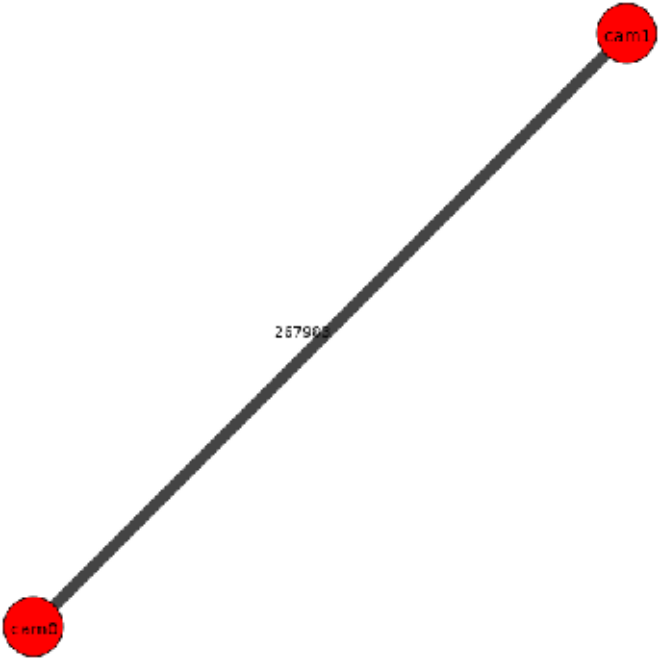
cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.ExtendedUnifiedCameraGeometry'>
distortion: [] +- []
projection: [0.57344449   1.19346756 288.57050796 289.31119708 315.98289269
200.0237574] +- [0.00842586 0.02254729 0.17245518 0.17442309 0.27722993 0.24411138]
reprojection error: [-0.000002, 0.000003] +- [0.130165, 0.115514]

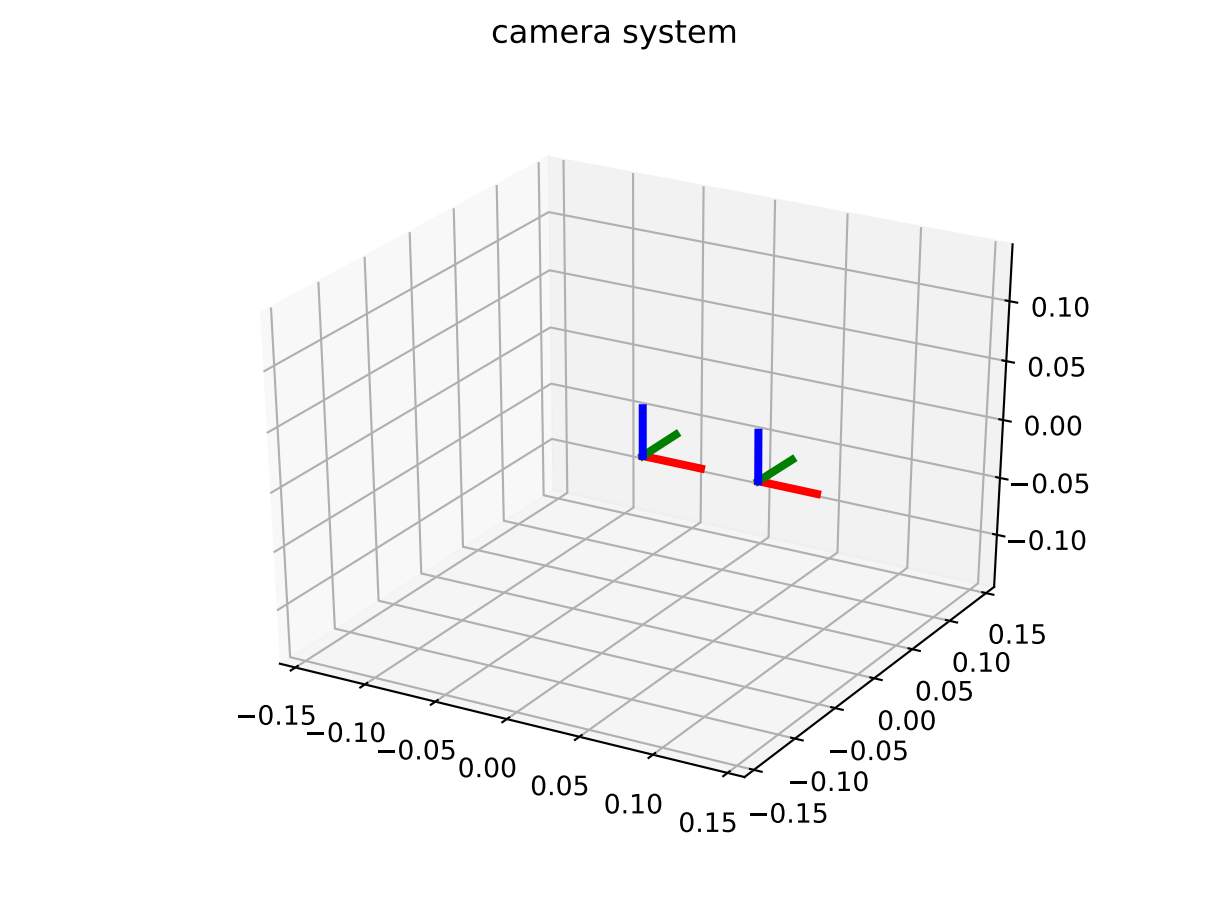
baseline T_1_0:
q: [-0.00222915 -0.00642756 -0.01219333 0.99990252] +- [0.00067384 0.00104855 0.00013343]
t: [-0.0804202   0.00005309 0.00010461] +- [0.00011747 0.00010981 0.00036219]

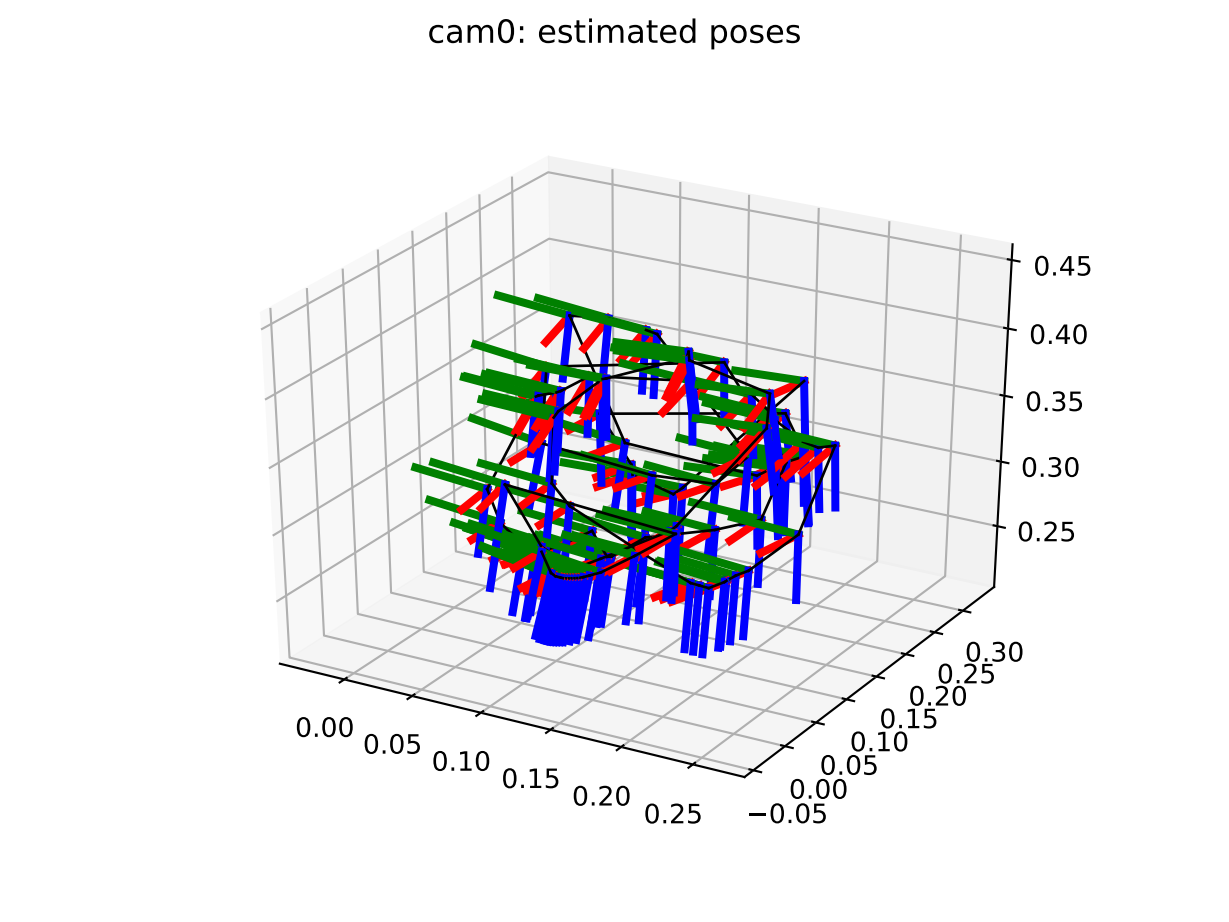
Target configuration
====================

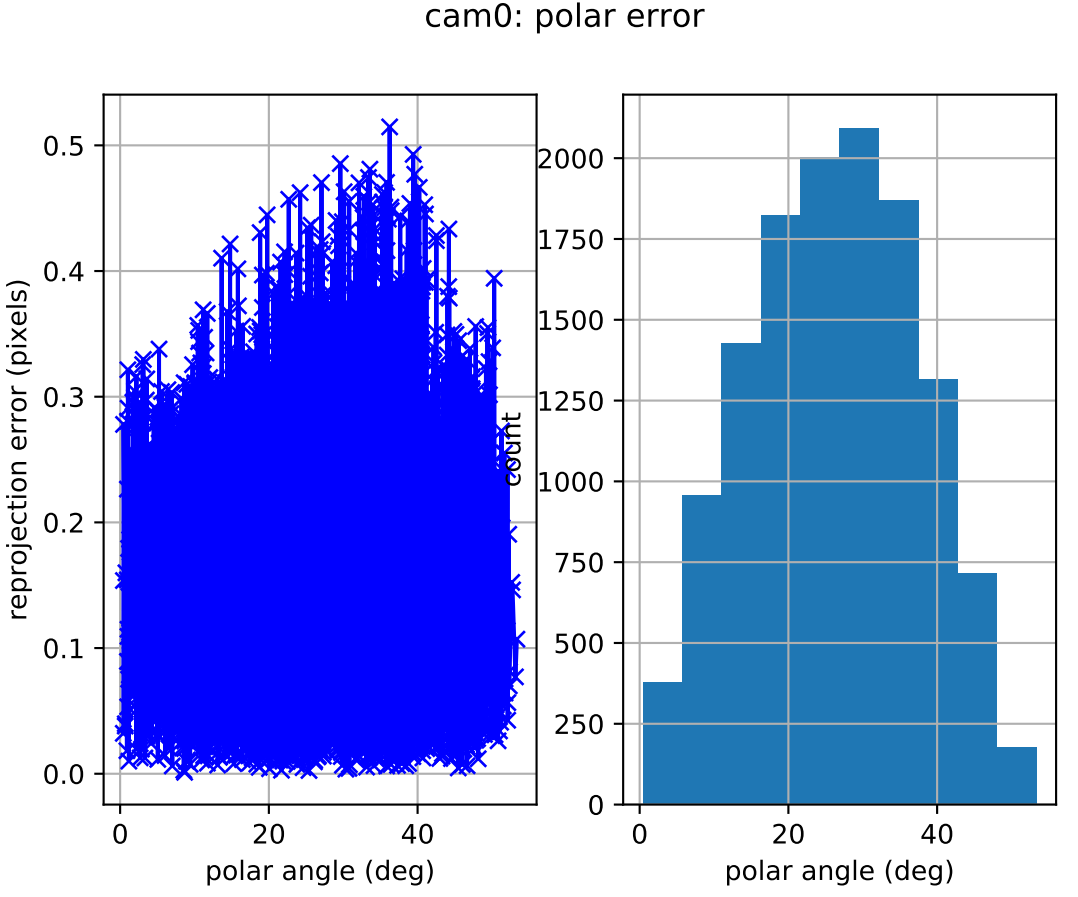
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0312 [m]
Spacing 0.00959999976 [m]

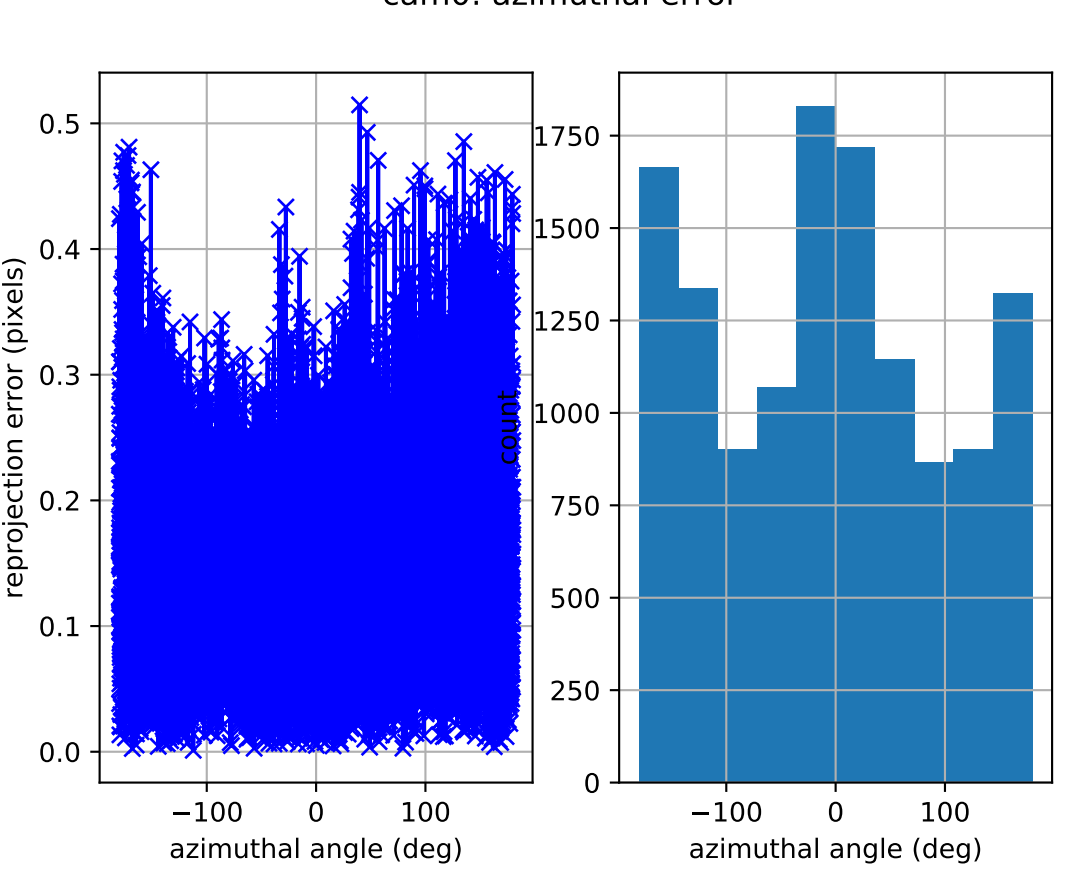
Inter-camera observations graph (edge weight=#mutual obs.)

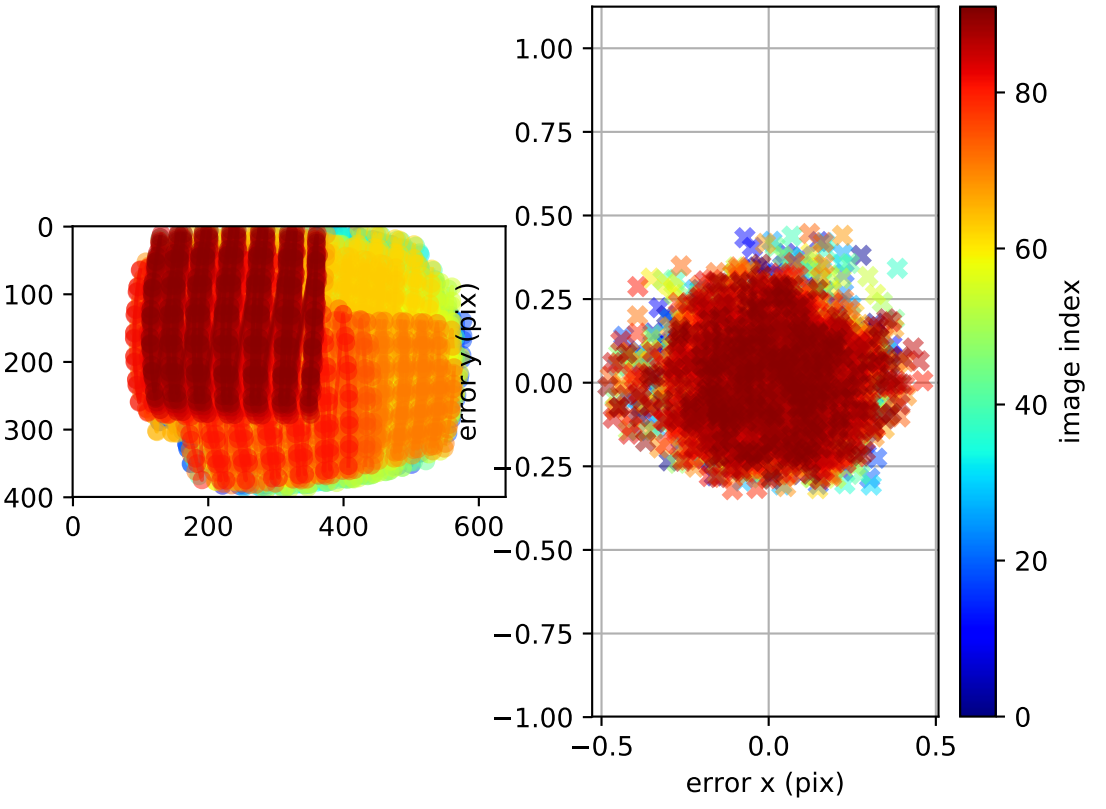


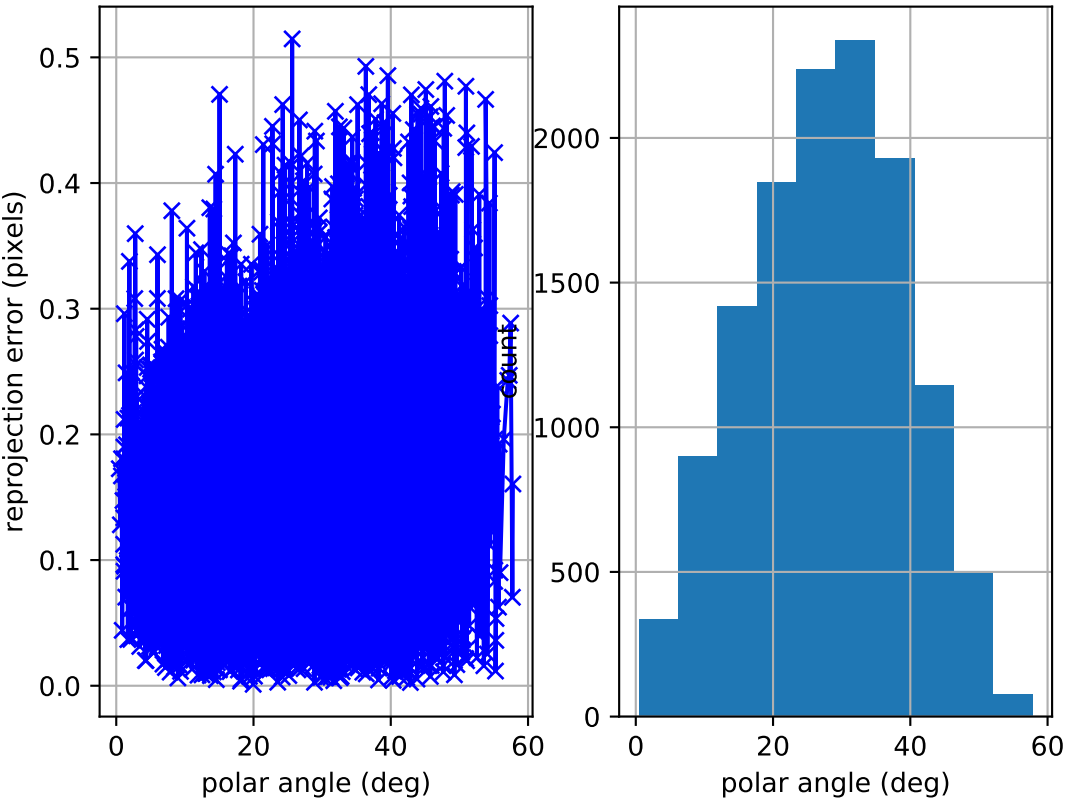

camera system
0.10
0.05
0.00
−0.05
−0.10
0.15
0.10
0.05
0.00
−0.05
−0.10
−0.15
−0.15
−0.10
−0.05
0.00
0.05
0.10
0.15

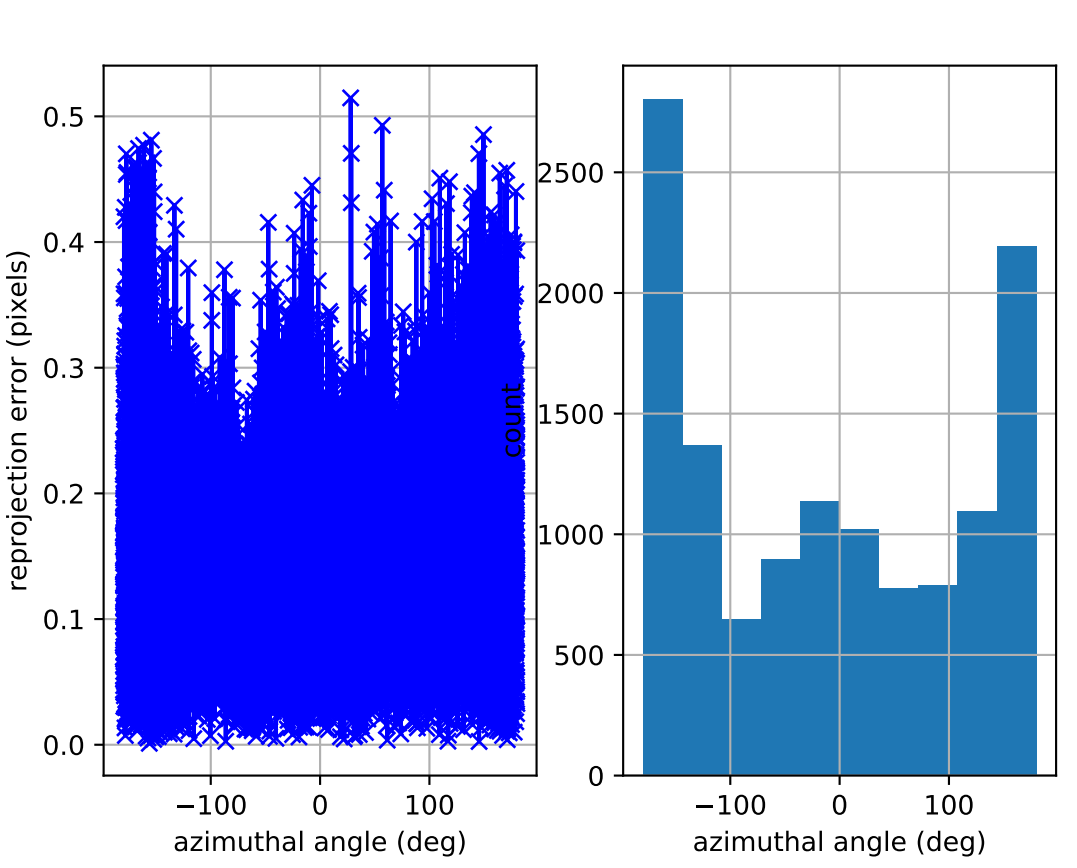

cam0: estimated poses
0.45
0.40
0.35
0.30
0.25
0.00
0.05
0.10
0.15
0.20
0.25
−0.05
0.00
0.05
0.10
0.15
0.20
0.25
0.30

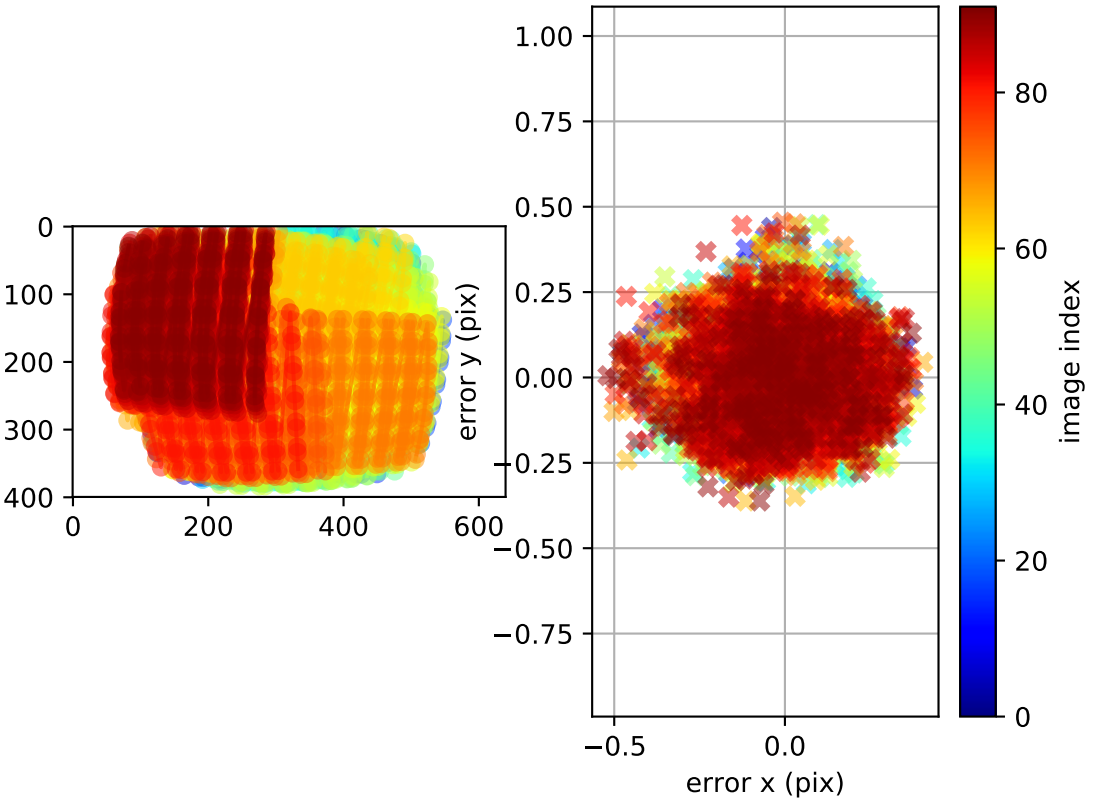

cam0: polar error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
0
20
40
polar angle (deg)
count
0
250
500
750
1000
1250
1500
1750
2000
0
20
40
polar angle (deg)

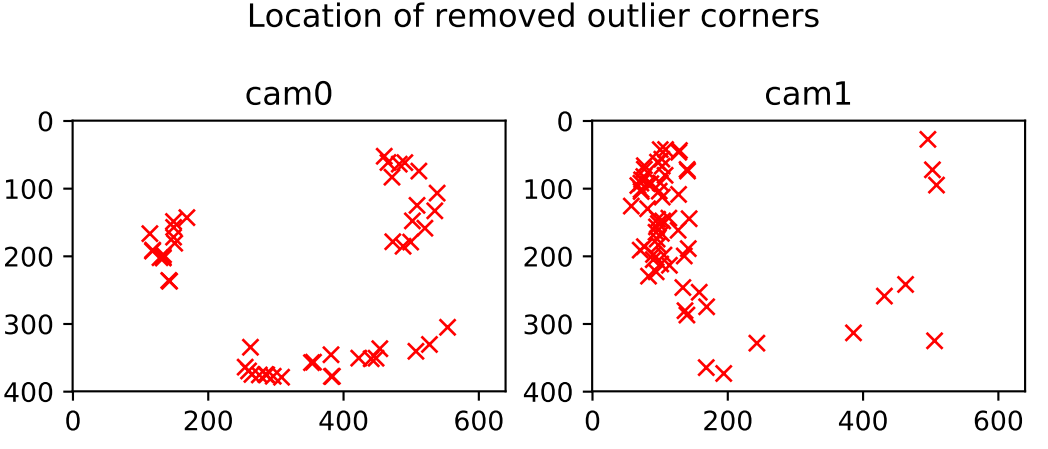

cam0: azimuthal error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
−100
0
100
azimuthal angle (deg)
count
0
250
500
750
1000
1250
1500
1750
−100
0
100
azimuthal angle (deg)


cam0: reprojection errors
0
100
200
300
400
0
200
400
600
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)
80
60
40
20
0
image index


cam1: polar error
reprojection error (pixels)
polar angle (deg)
count
polar angle (deg)
0.0
0.1
0.2
0.3
0.4
0.5
0
20
40
60
0
500
1000
1500
2000


cam1: azimuthal error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0.5
−100
0
100
azimuthal angle (deg)
count
0
500
1000
1500
2000
2500
−100
0
100
azimuthal angle (deg)


cam1: reprojection errors
0
100
200
300
400
0
200
400
600
error y (pix)
1.00
0.75
0.50
0.25
0.00
−0.25
−0.50
−0.75
−0.5
0.0
error x (pix)
80
60
40
20
0
image index


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