Calibration results
====================
Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [0.01709277 -0.20037691 0.75199831 -0.90258125] +- [0.01089111 0.06325429 0.08700861 0.08000316]
projection: [287.81979757 287.64116912 318.09098039 201.47164968] +- [0.12937139 0.12864815 0.52113421
0.47977813]
reprojection error: [-0.000008, 0.000003] +- [0.106901, 0.103339]

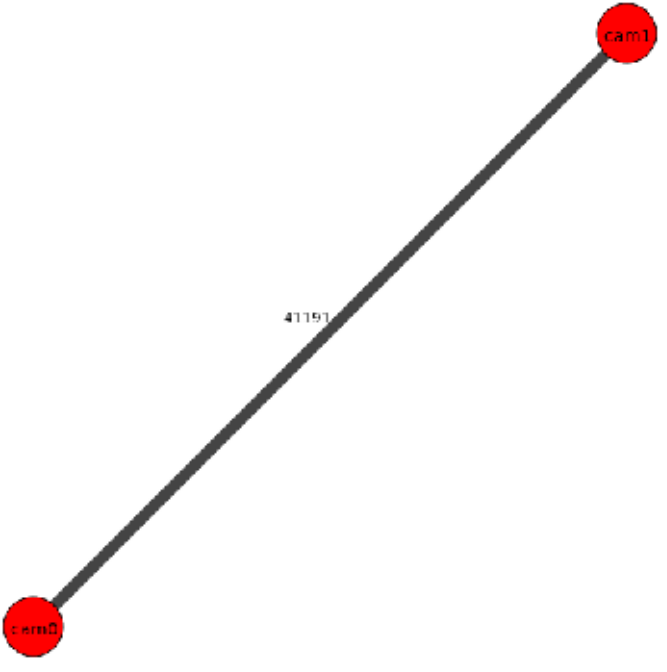
cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [-0.01260017 0.05525912 -0.11014366 0.08685302] +- [0.01451713 0.11650385 0.35879676 0.37347842]
projection: [288.15260272 287.76024478 317.10515954 201.19450557] +- [0.12344362 0.13151921 0.52810988
0.45708843]
reprojection error: [0.000007, 0.000000] +- [0.096254, 0.100580]

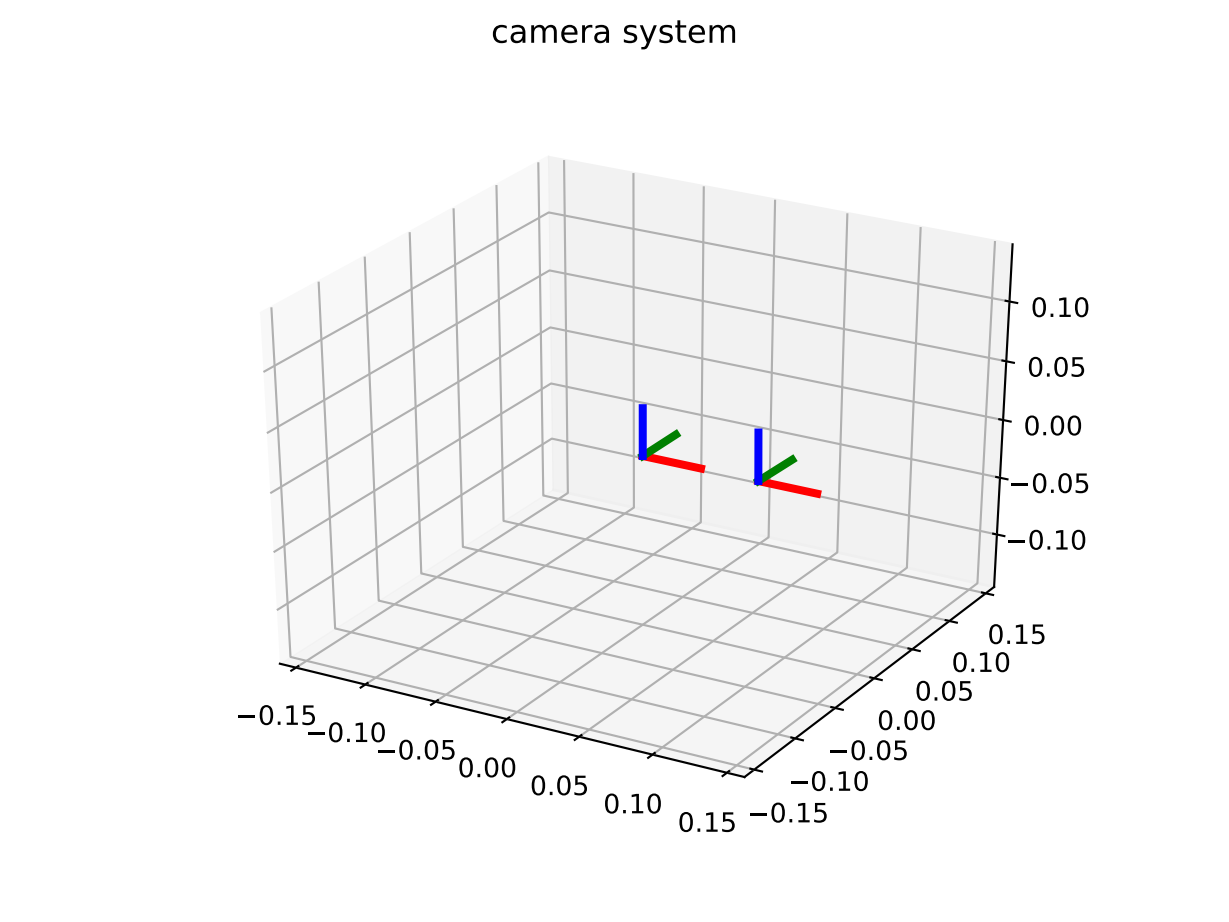
baseline T_1_0:
q: [-0.00300223 -0.0077971 -0.01230951 0.99988933] +- [0.00185978 0.00208671 0.00020963]
t: [-0.08064507 -0.00012725 0.00028193] +- [0.00024192 0.00022005 0.00054652]

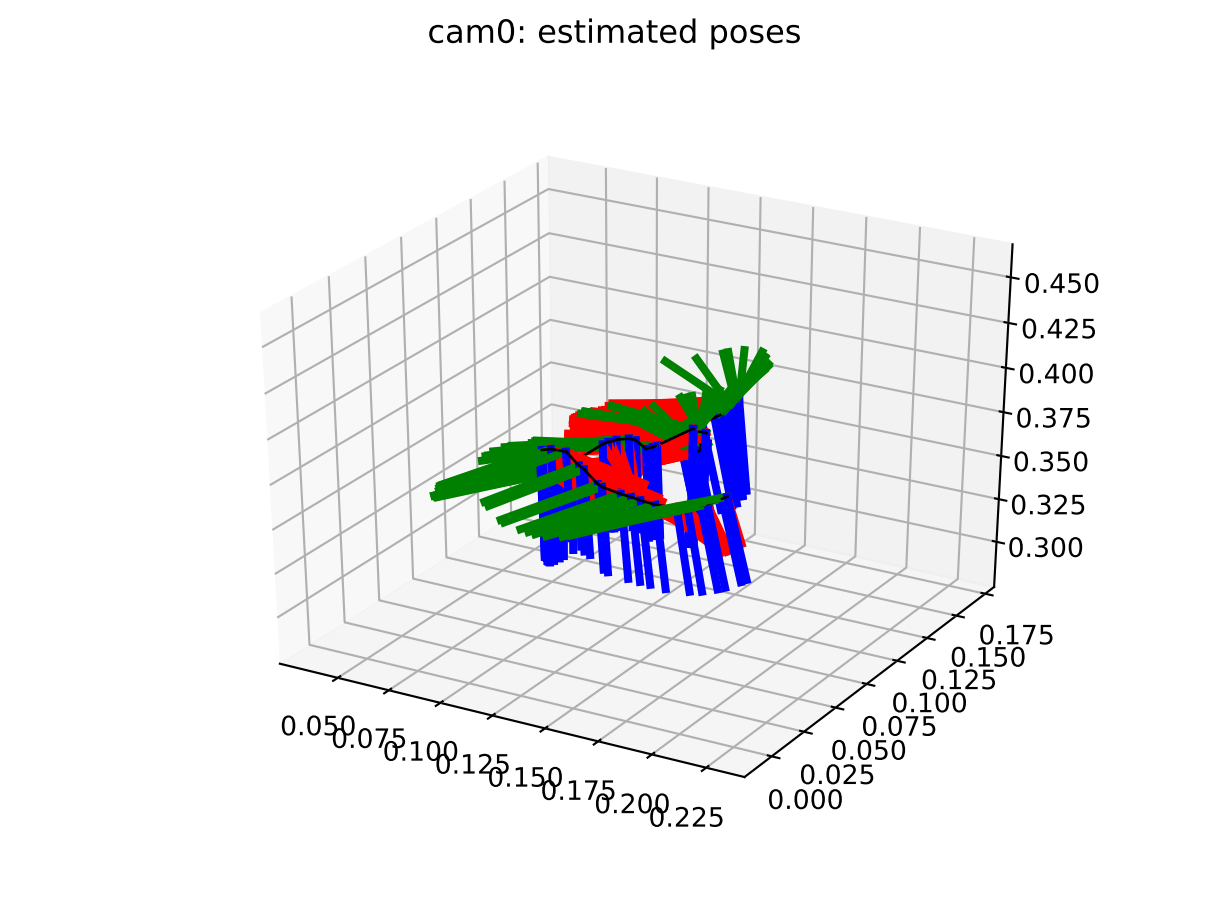
Target configuration
====================

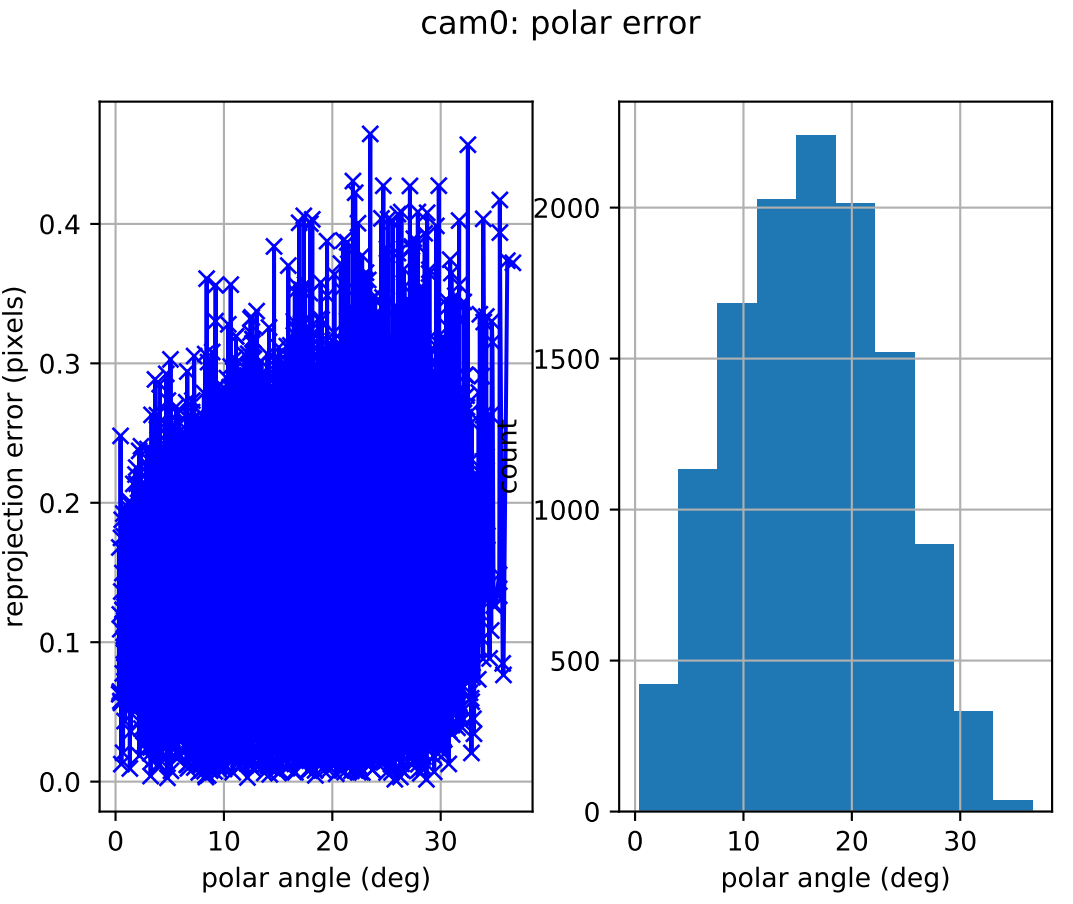
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0312 [m]
Spacing 0.00959999976 [m]

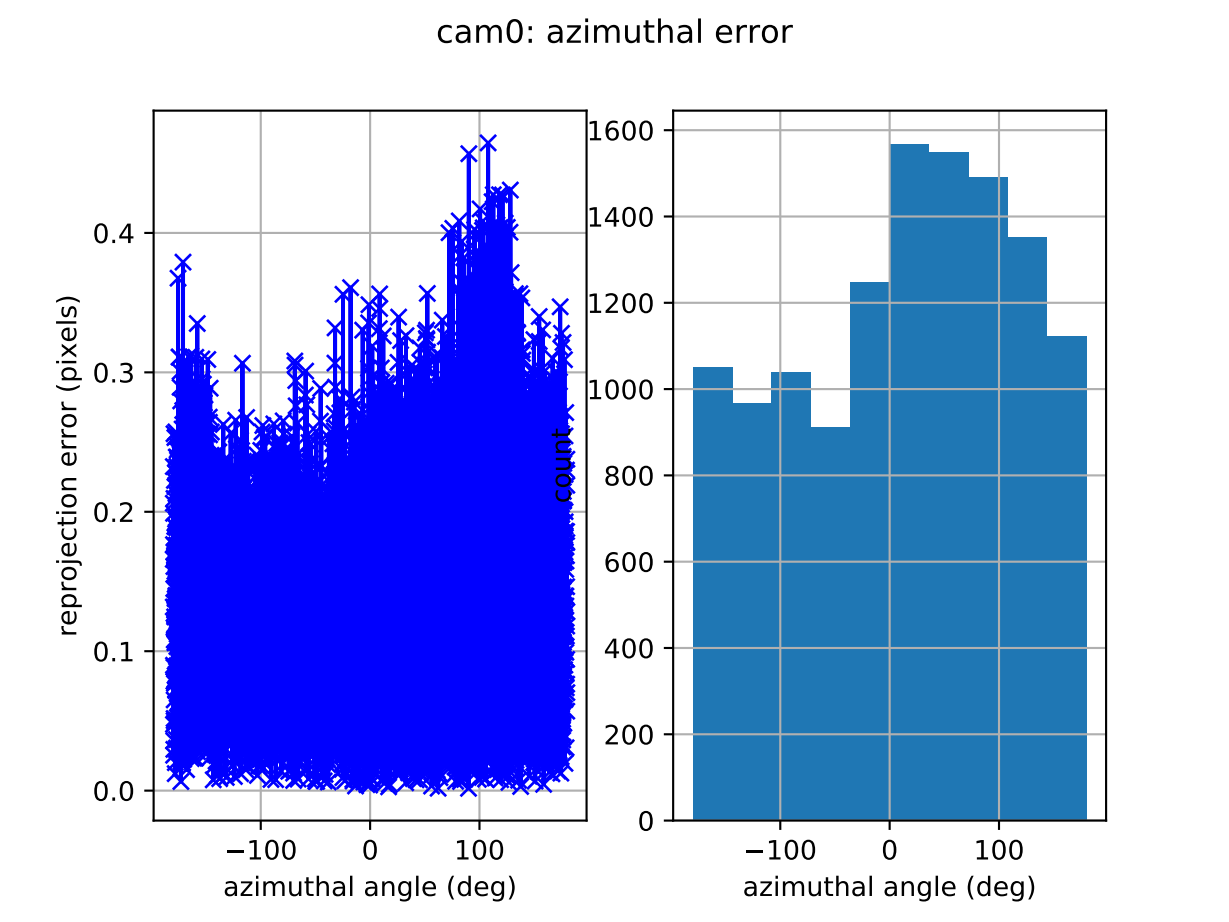
Inter-camera observations graph (edge weight=#mutual obs.)

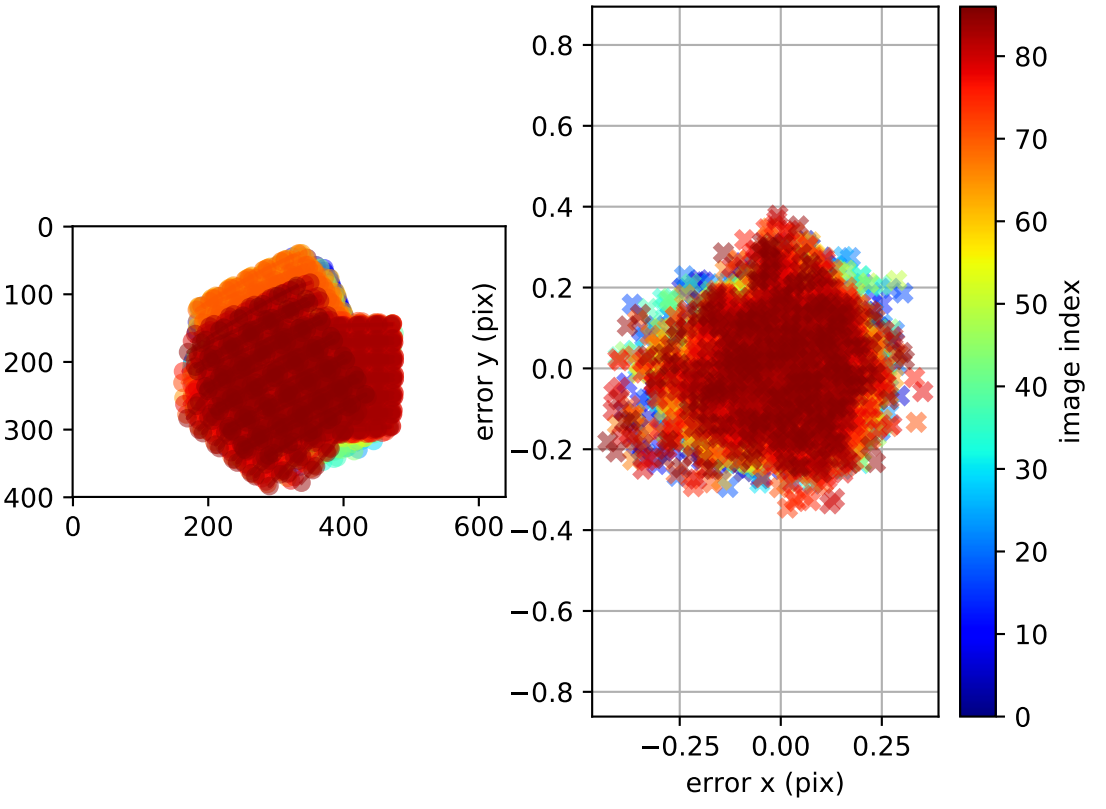


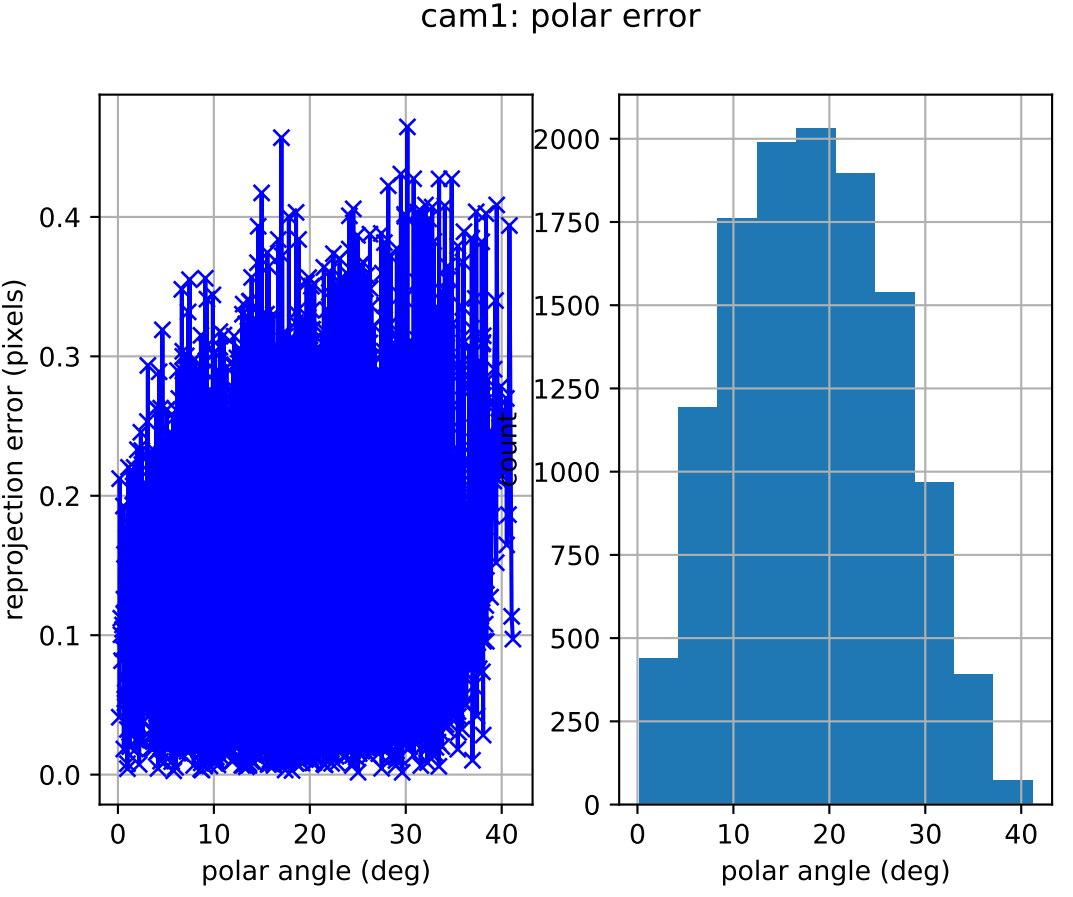

camera system
0.10
0.05
0.00
−0.05
−0.10
0.15
0.10
0.05
0.00
−0.05
−0.10
−0.15
−0.15
−0.10
−0.05
0.00
0.05
0.10
0.15

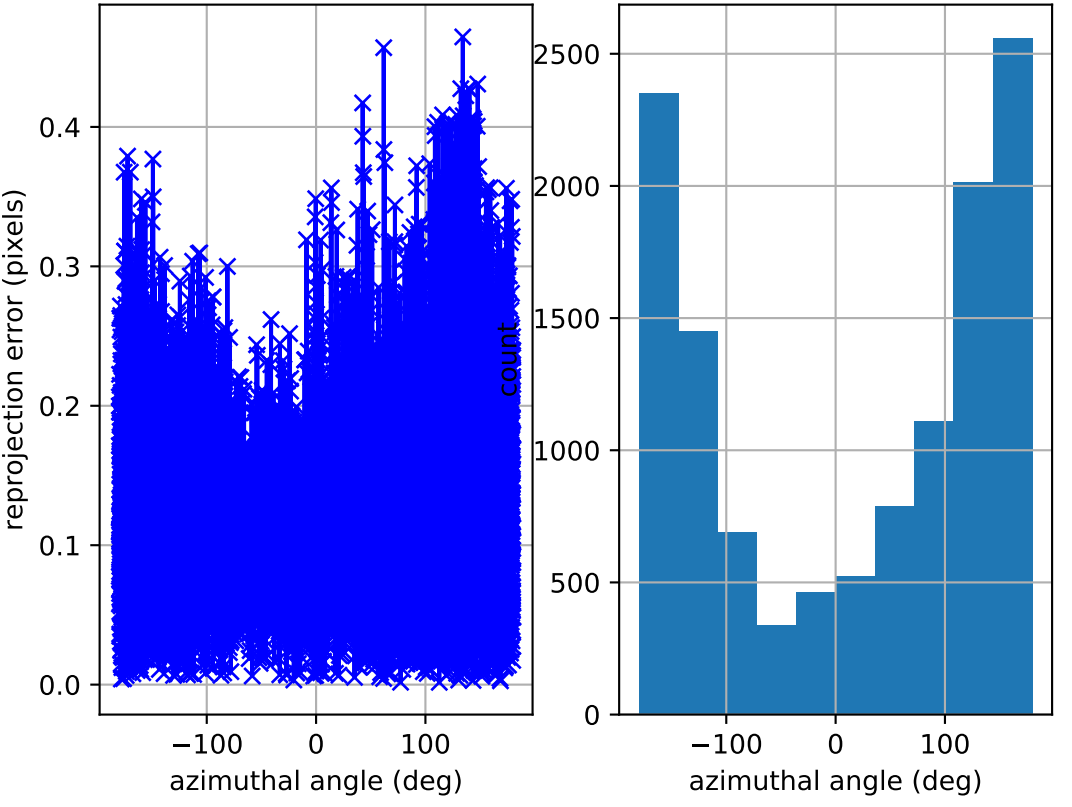

cam0: estimated poses
0.450
0.425
0.400
0.375
0.350
0.325
0.300
0.175
0.150
0.125
0.100
0.075
0.050
0.025
0.000
0.050
0.075
0.100
0.125
0.150
0.175
0.200
0.225

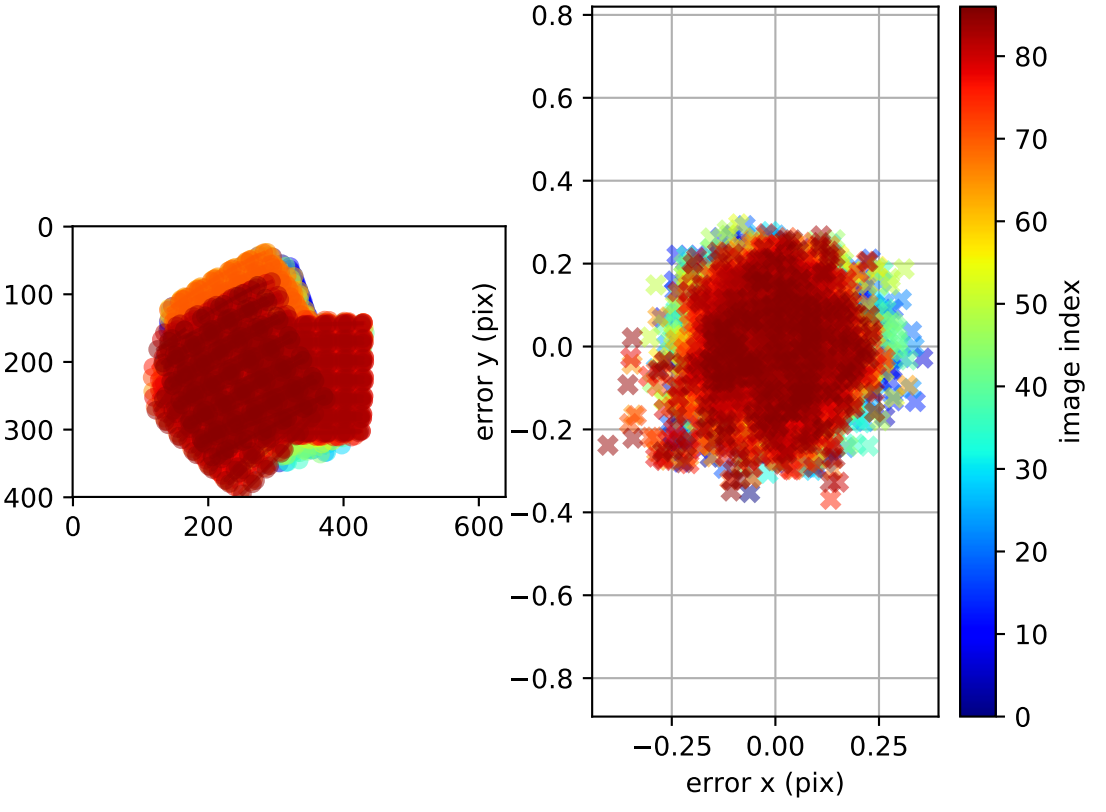

cam0: polar error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0
10
20
30
polar angle (deg)
count
0
500
1000
1500
2000
0
10
20
30
polar angle (deg)

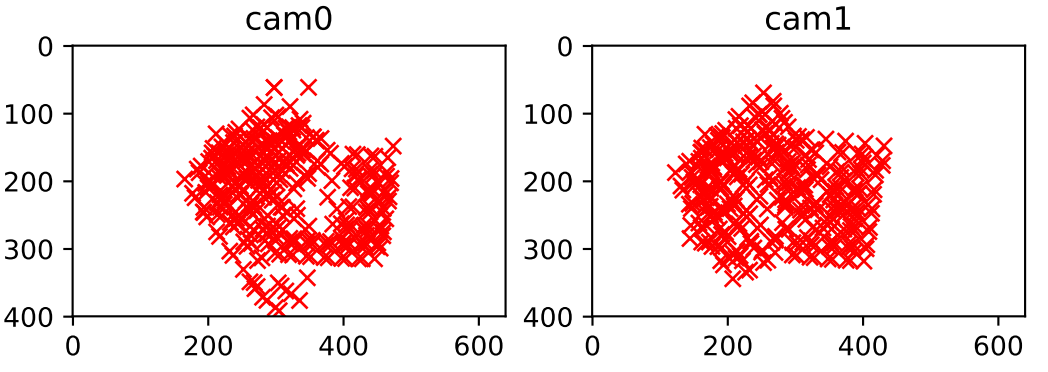

cam0: azimuthal error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
−100
0
100
azimuthal angle (deg)
count
0
200
400
600
800
1000
1200
1400
1600
−100
0
100
azimuthal angle (deg)


cam0: reprojection errors
0
100
200
300
400
0
200
400
600
error y (pix)
0.8
0.6
0.4
0.2
0.0
−0.2
−0.4
−0.6
−0.8
−0.25
0.00
0.25
error x (pix)
80
70
60
50
40
30
20
10
0
image index


cam1: polar error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
0
10
20
30
40
polar angle (deg)
count
0
250
500
750
1000
1250
1500
1750
2000
0
10
20
30
40
polar angle (deg)


cam1: azimuthal error
reprojection error (pixels)
0.0
0.1
0.2
0.3
0.4
−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)
0.8
0.6
0.4
0.2
0.0
−0.2
−0.4
−0.6
−0.8
−0.25
0.00
0.25
error x (pix)
80
70
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