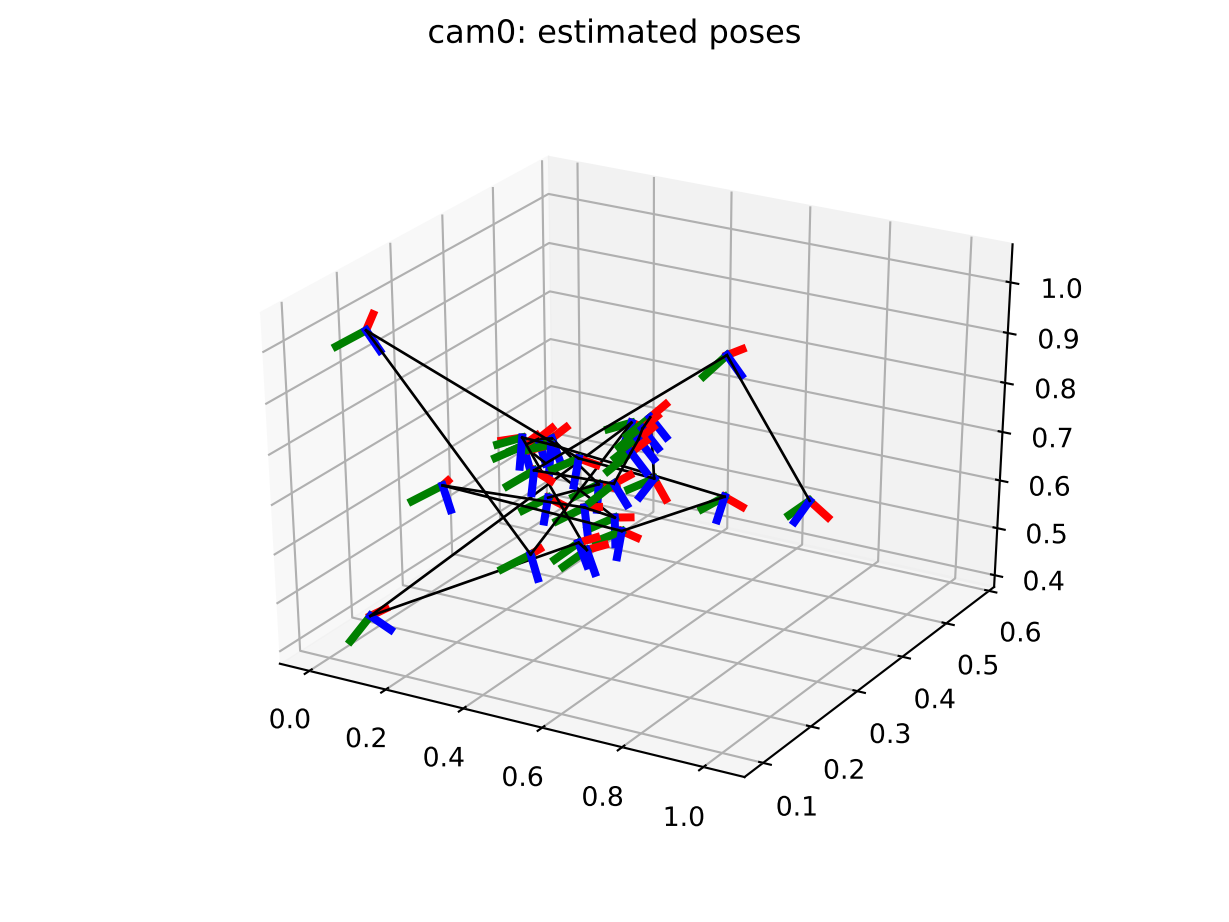
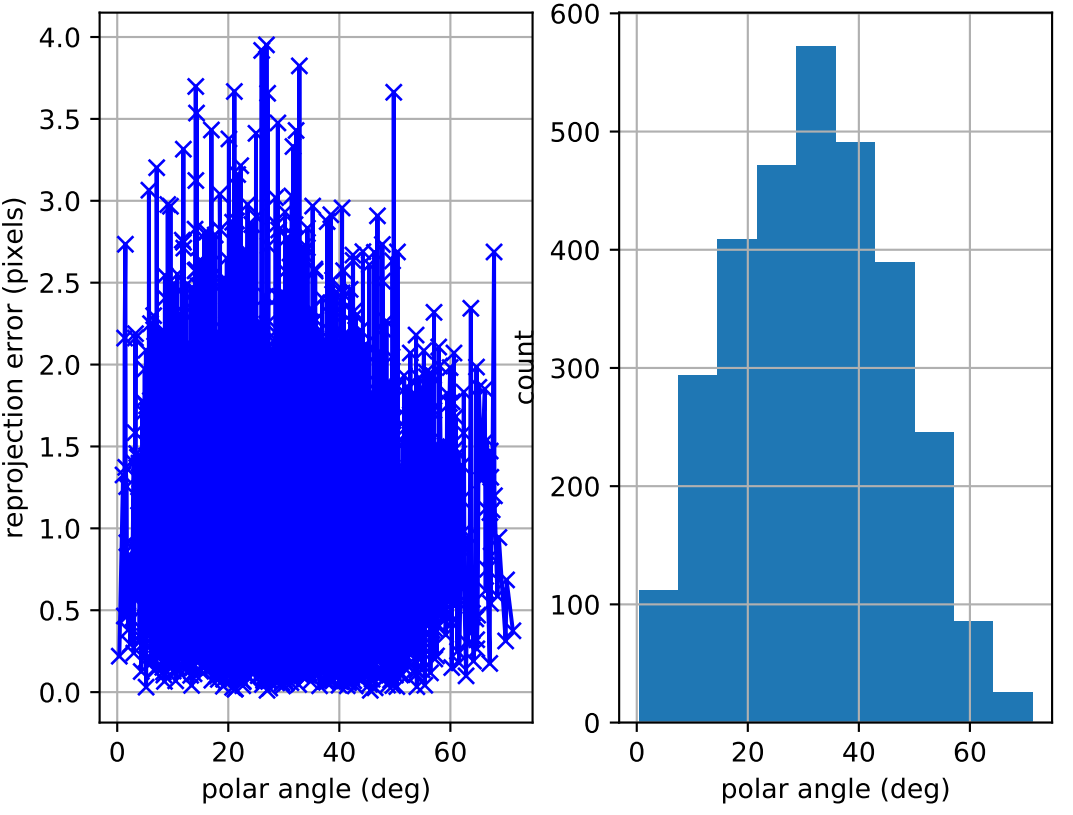
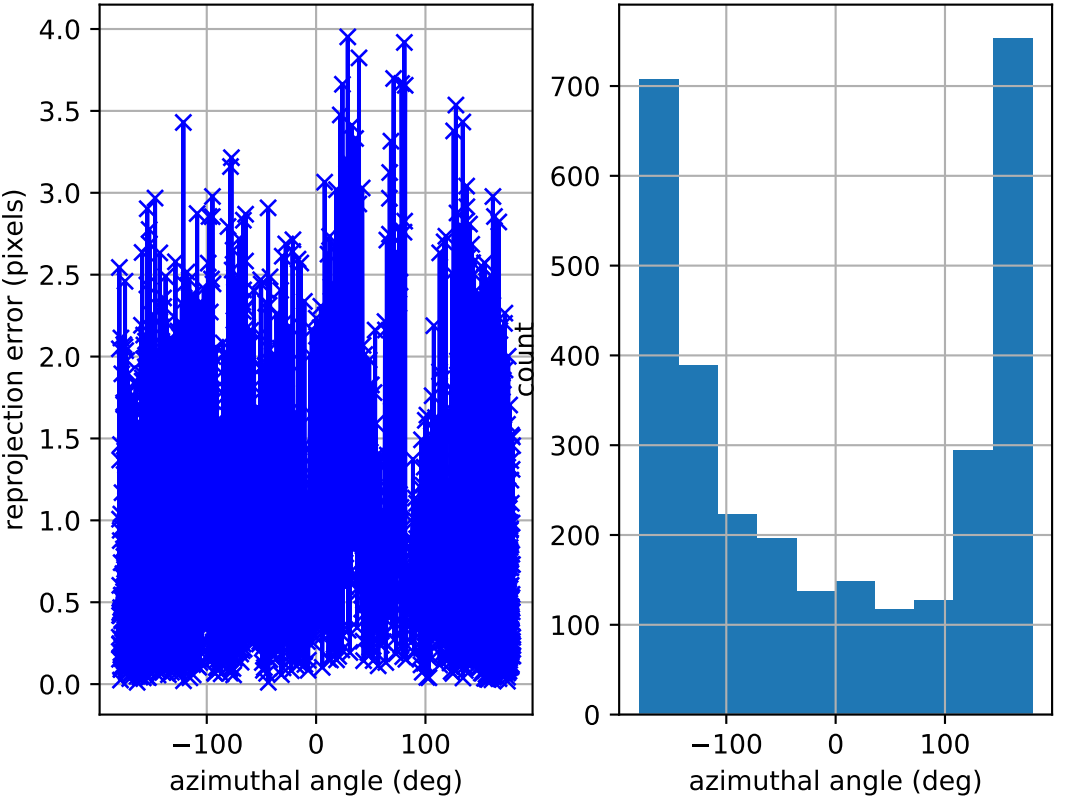
Calibration results
====================
Camera-system parameters:
cam0 (/feature_tracker_imu/camB):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [-0.01081561 0.02622355 -0.02233025 0.00719382] +- [0.00364271 0.00922047 0.00926843 0.00313928]
projection: [563.25314164 563.15776573 664.11854298 404.4646717] +- [0.84276179 0.79729357 0.54035851 0.44305973]
reprojection error: [0.000001, 0.000000] +- [0.817259, 0.668424]

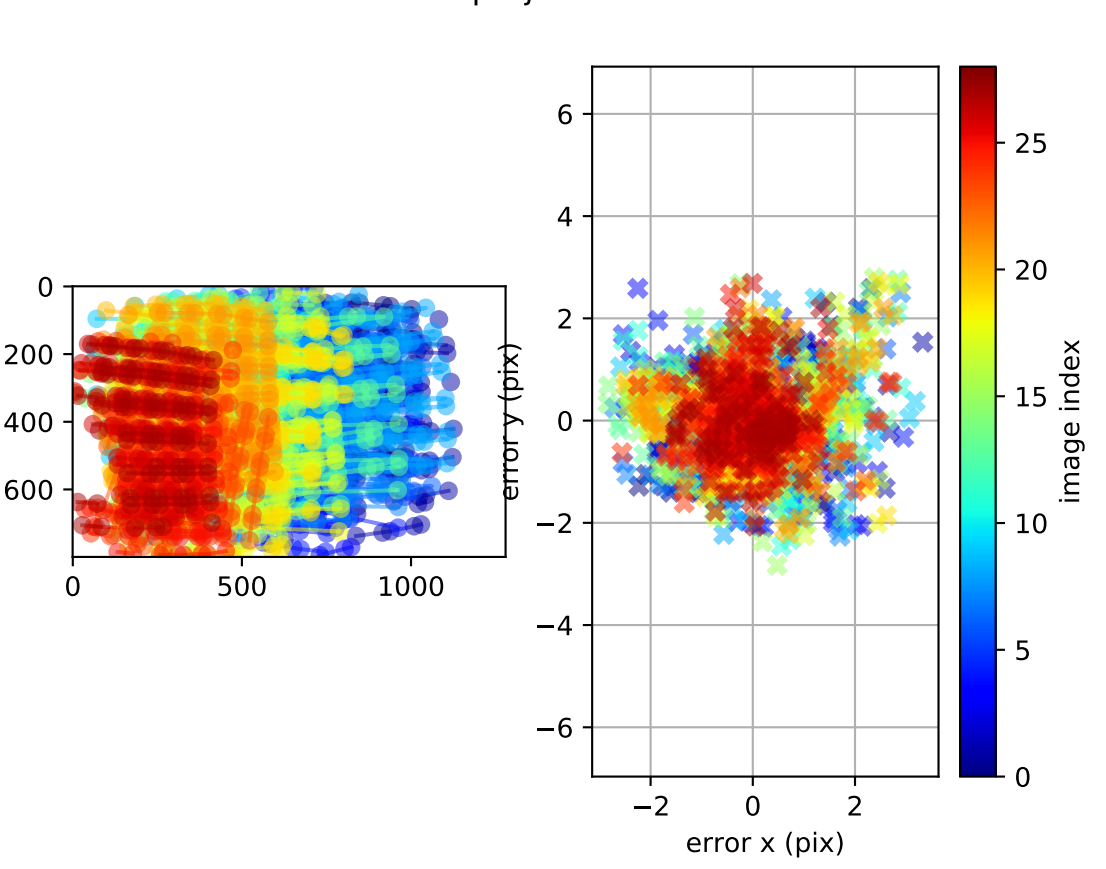
Target configuration
====================

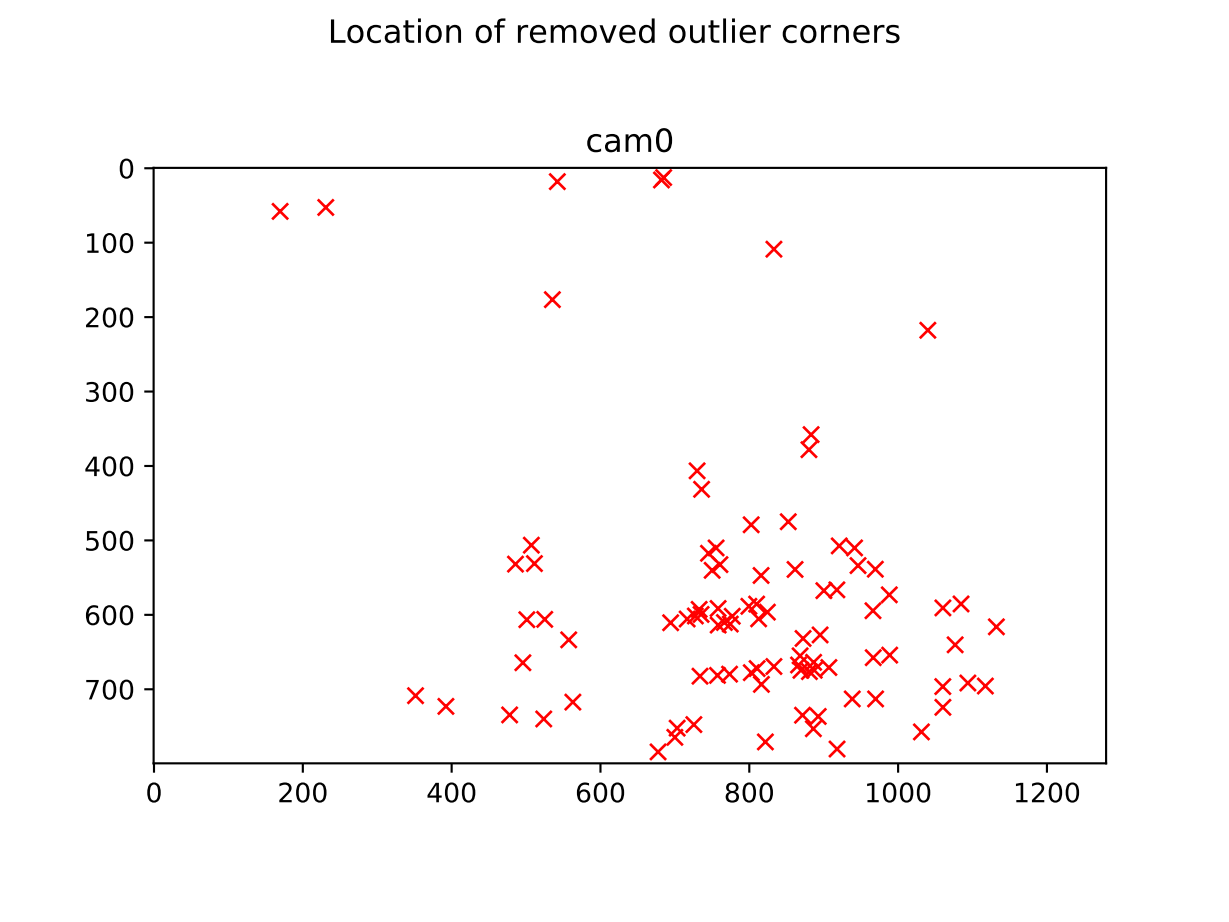
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0922 [m]
Spacing 0.02766 [m]


cam0: estimated poses
1.0
0.9
0.8
0.7
0.6
0.5
0.4
0.6
0.5
0.4
0.3
0.2
0.1
0.0
0.2
0.4
0.6
0.8
1.0


cam0: polar error
reprojection error (pixels)
polar angle (deg)
count
polar angle (deg)
0.0
0.5
1.0
1.5
2.0
2.5
3.0
3.5
4.0
0
20
40
60
0
100
200
300
400
500
600


cam0: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)
0.0
0.5
1.0
1.5
2.0
2.5
3.0
3.5
4.0
−100
0
100
0
100
200
300
400
500
600
700
−100
0
100


cam0: reprojection errors
0
200
400
600
0
500
1000
6
4
2
0
−2
−4
−6
error y (pix)
−2
0
2
error x (pix)
25
20
15
10
5
0
image index


Location of removed outlier corners
cam0
0
100
200
300
400
500
600
700
0
200
400
600
800
1000
1200