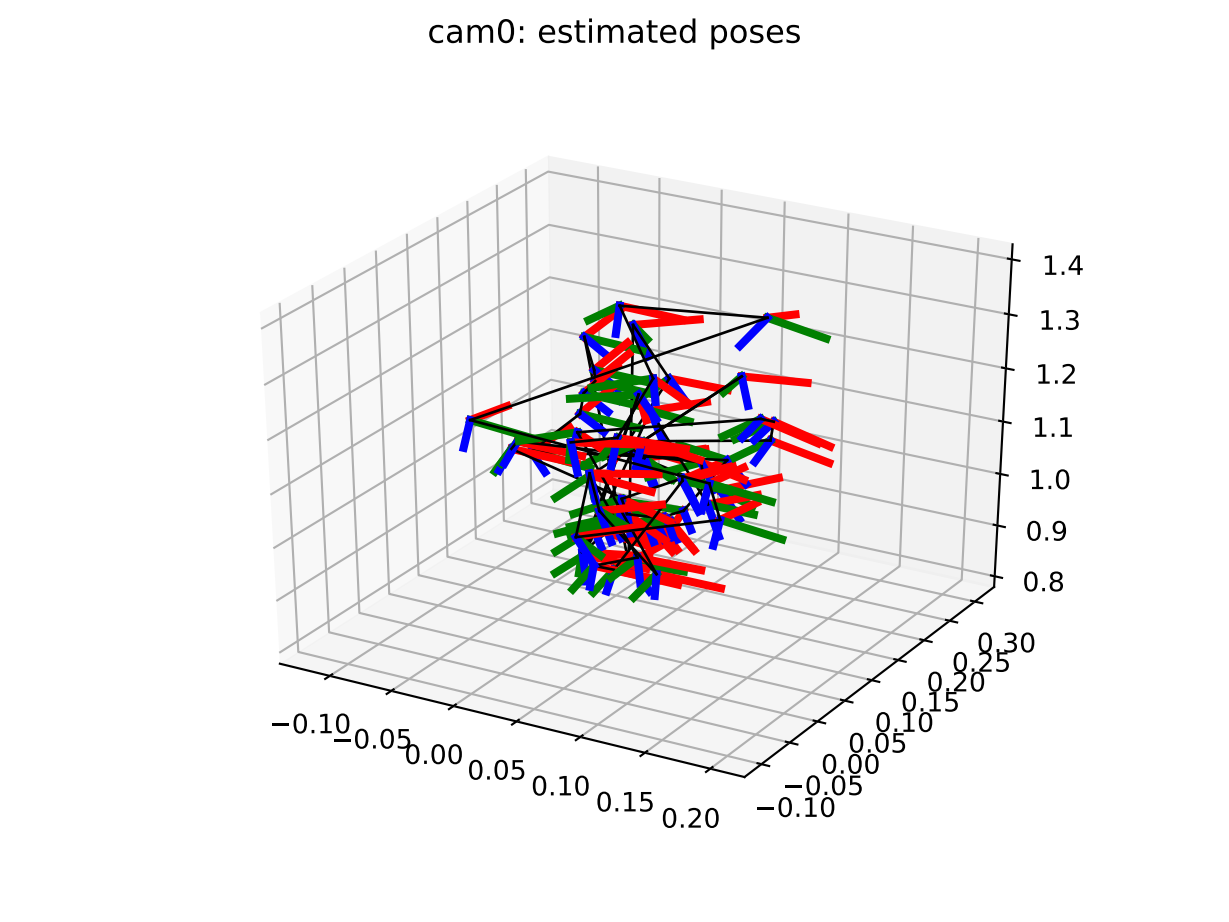
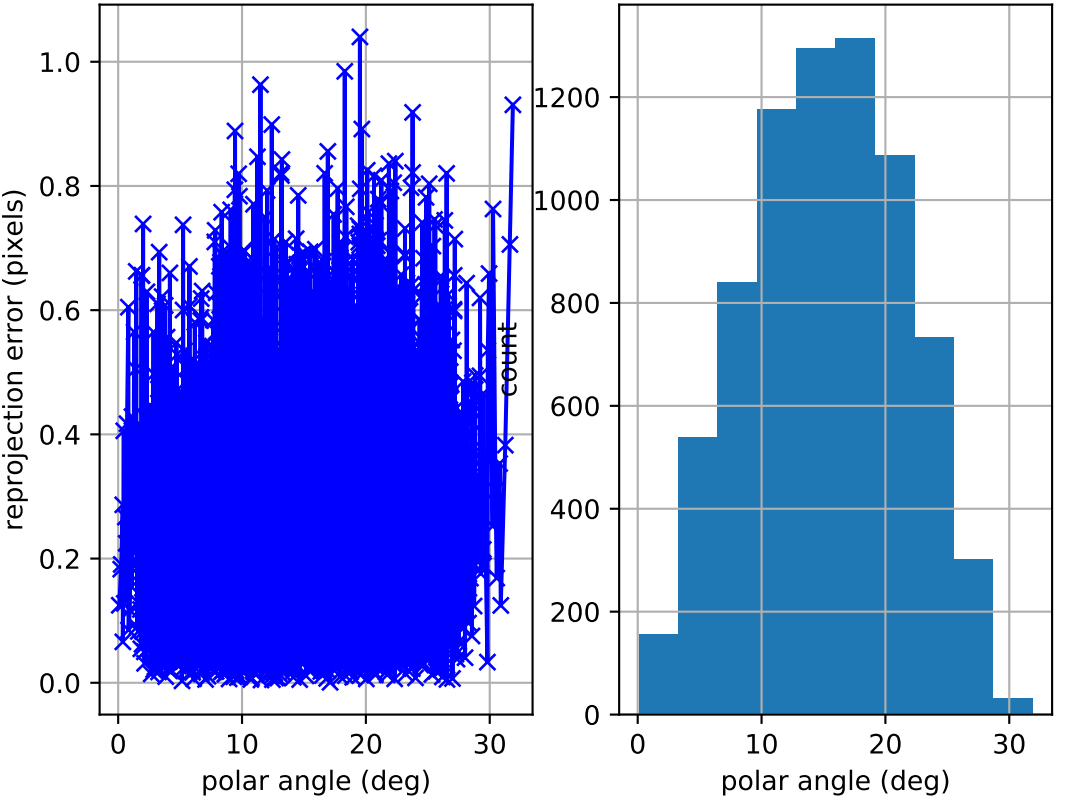
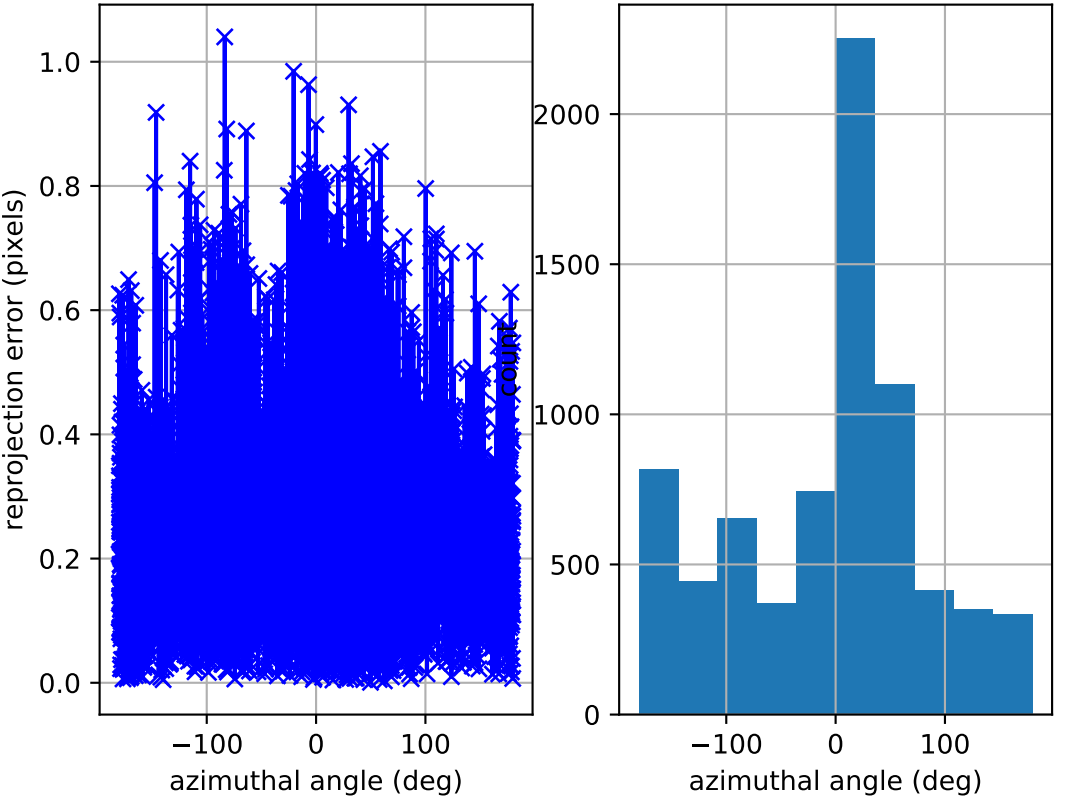
Calibration results
==========
Camera-system parameters:
cam0 (/color/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.08852753 -0.22599448 -0.00015262 0.00056625] +- [0.01271195 0.02384175 0.00159536 0.00104253]
projection: [863.72802427 863.22223205 637.52399913 385.52910358] +- [13.55285202 13.55997013 3.43951007
5.25161808]
reprojection error: [-0.000007, -0.000004] +- [0.203078, 0.198977]

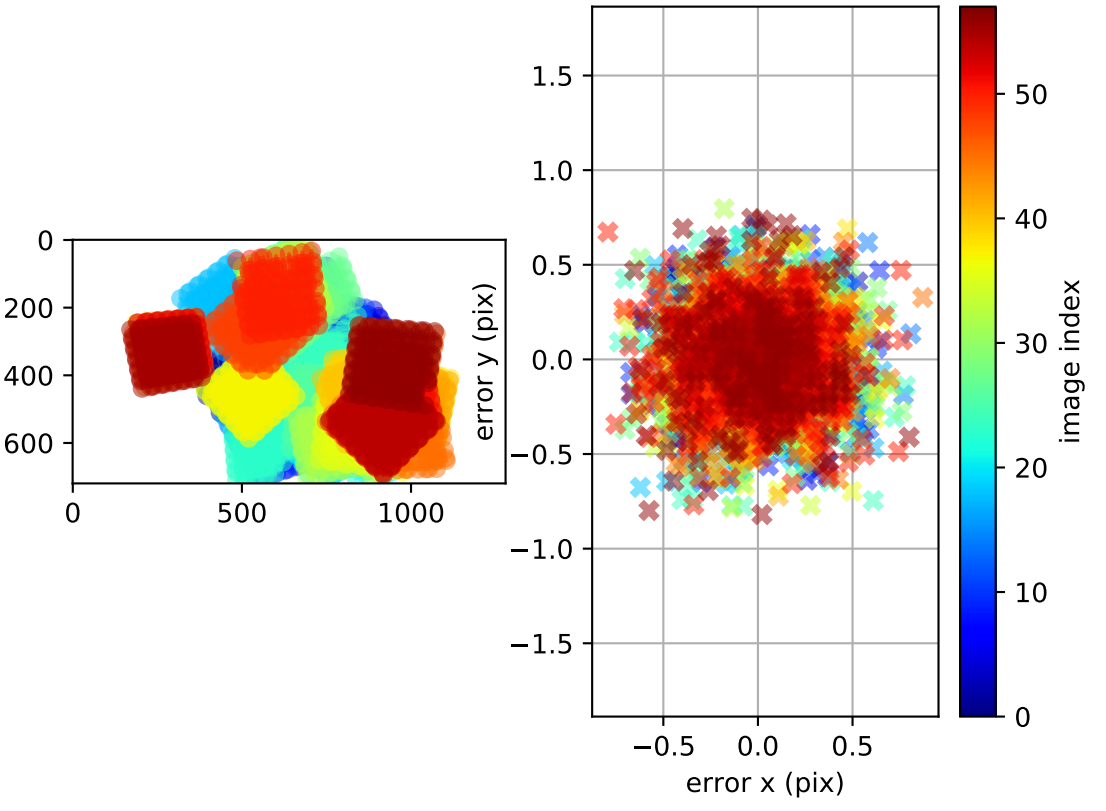
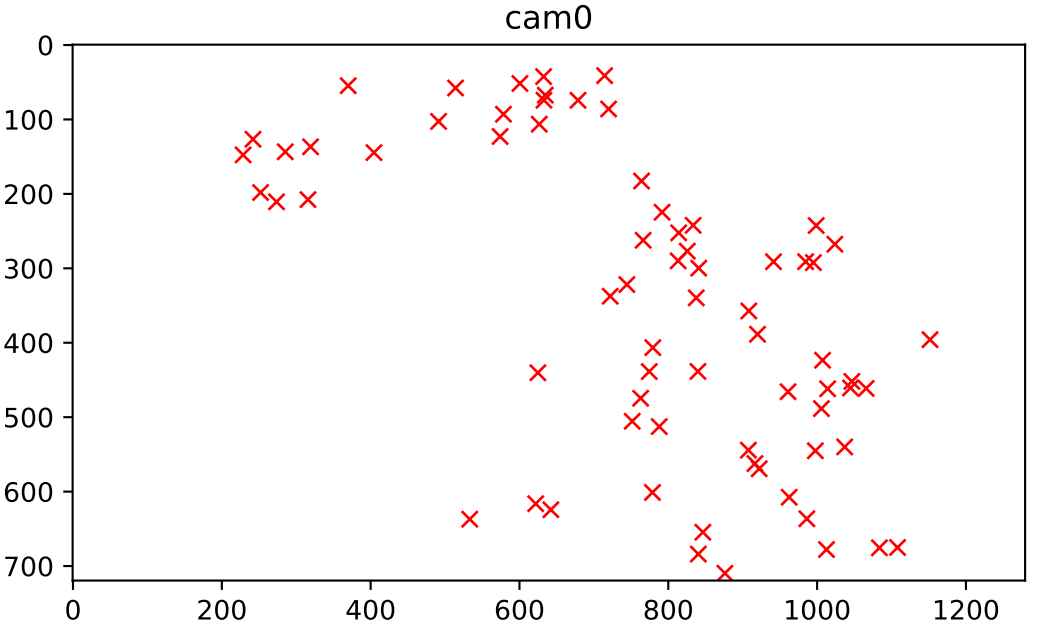
Target configuration
==========

Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.03 [m]
Spacing 0.009 [m]


cam0: estimated poses
1.4
1.3
1.2
1.1
1.0
0.9
0.8
0.30
0.25
0.20
0.15
0.10
0.05
0.00
−0.05
−0.10
−0.10
−0.05
0.00
0.05
0.10
0.15
0.20


cam0: polar error
reprojection error (pixels)
1.0
0.8
0.6
0.4
0.2
0.0
0
10
20
30
polar angle (deg)
count
1200
1000
800
600
400
200
0
0
10
20
30
polar angle (deg)


cam0: azimuthal error
reprojection error (pixels)
azimuthal angle (deg)
count
azimuthal angle (deg)
0.0
0.2
0.4
0.6
0.8
1.0
−100
0
100
0
500
1000
1500
2000


cam0: reprojection errors
0
200
400
600
0
500
1000
error y (pix)
1.5
1.0
0.5
0.0
−0.5
−1.0
−1.5
−0.5
0.0
0.5
error x (pix)
50
40
30
20
10
0
image index

Location of removed outlier corners