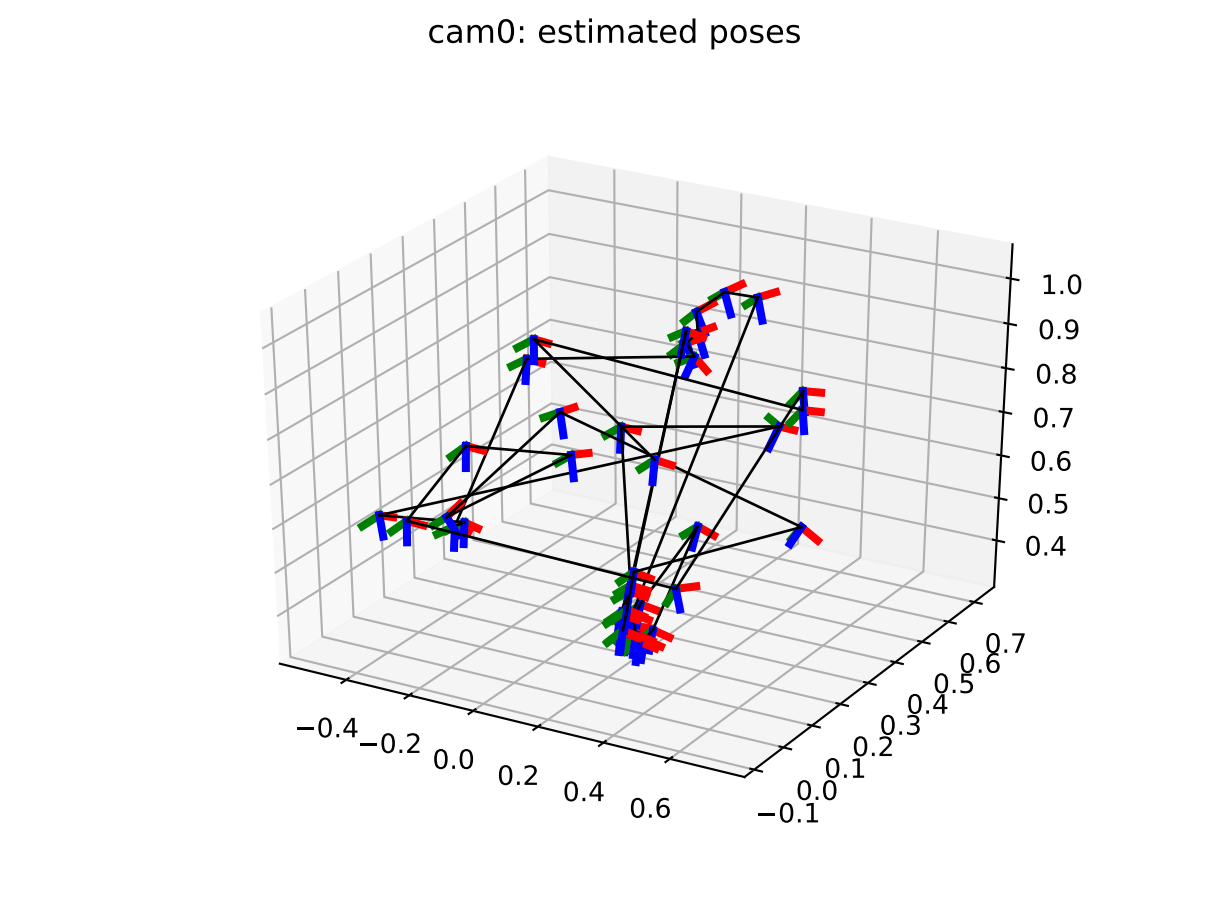
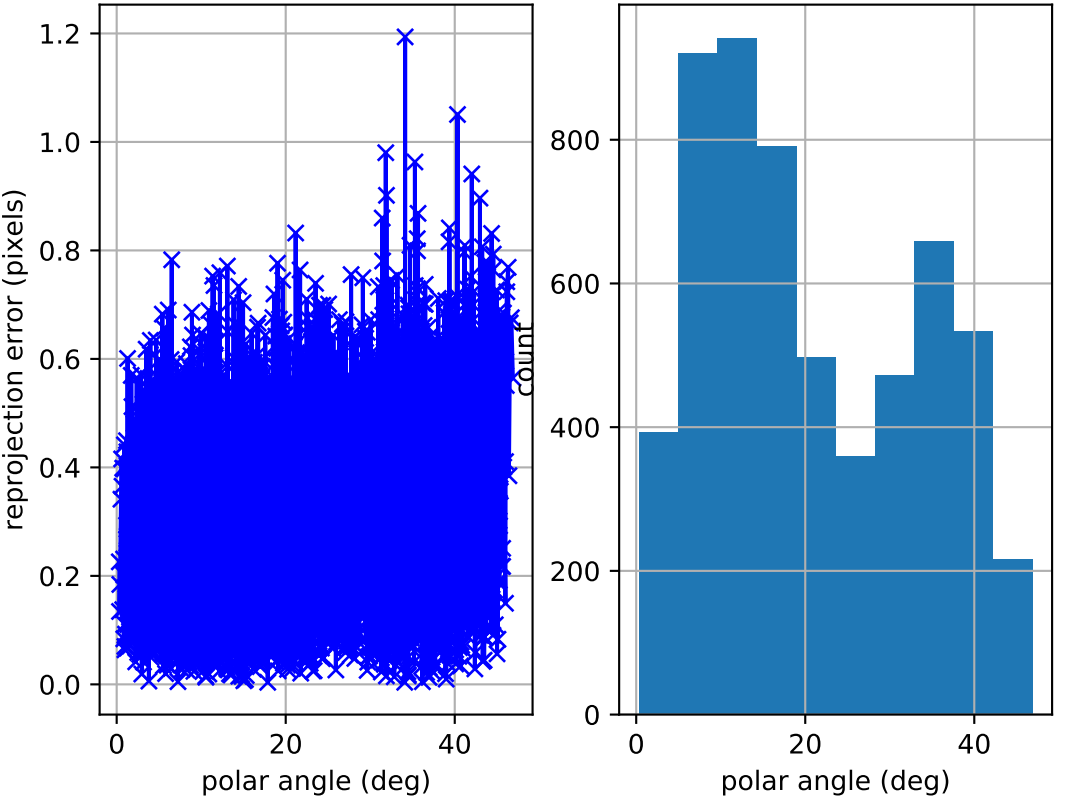
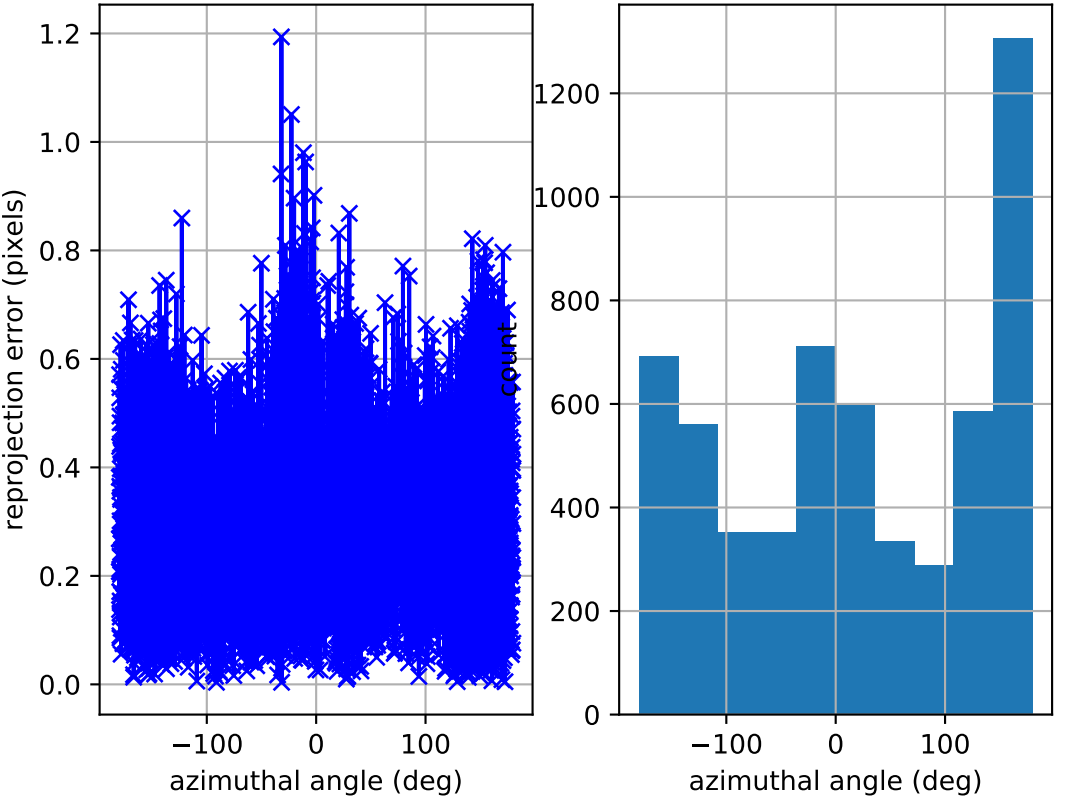
Calibration results
====================
Camera-system parameters:
cam0 (/INTELcam/color/image_raw_throttled):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [-0.04468274 0.02495243 -0.00006465 0.00100516] +- [0.00205081 0.00152141 0.00050378 0.00052237]
projection: [637.01022351 636.56719507 653.63788593 362.88548799] +- [4.77011214 4.59450086 1.80898739
1.29884335]
reprojection error: [-0.000000, 0.000000] +- [0.245558, 0.238934]

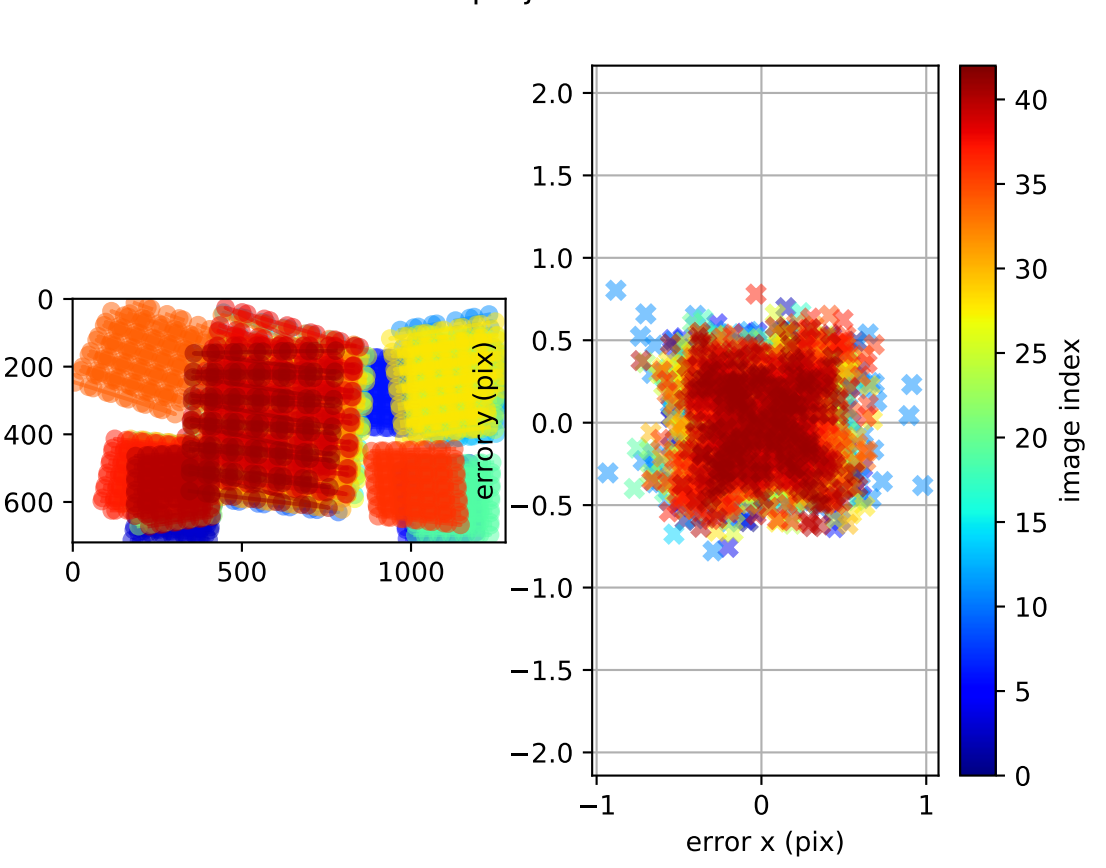
Target configuration
====================

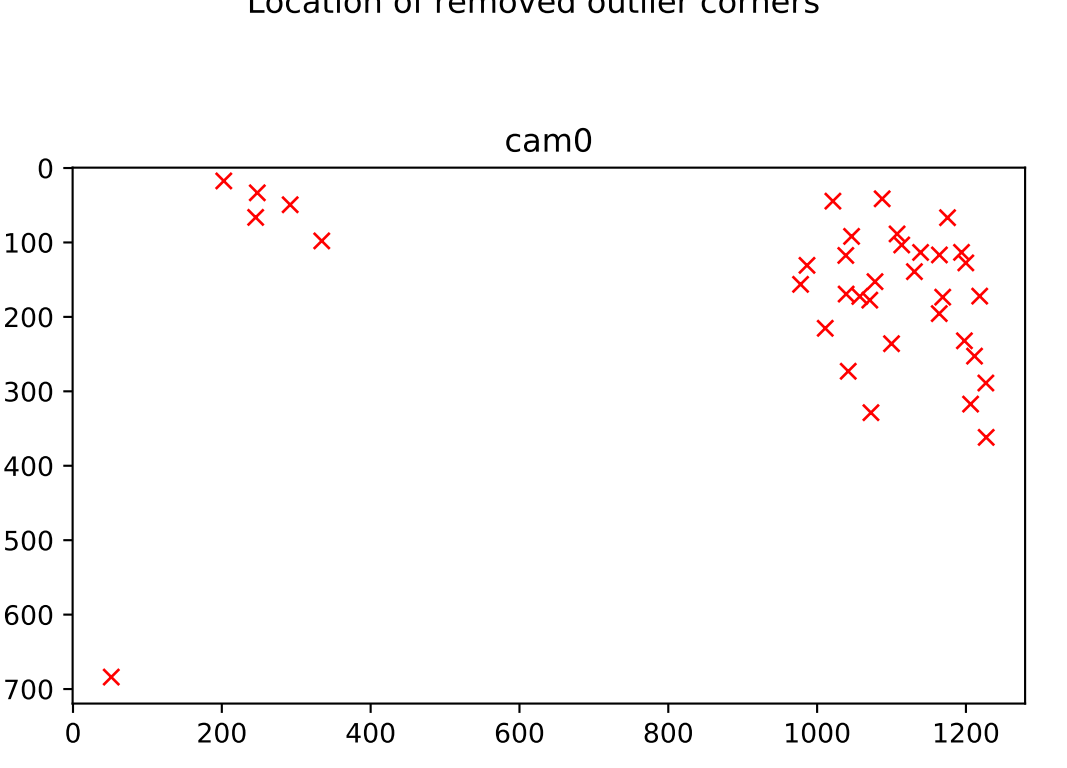
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0352 [m]
Spacing 0.01056 [m]


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


cam0: polar error
reprojection error (pixels)
1.2
1.0
0.8
0.6
0.4
0.2
0.0
0
20
40
polar angle (deg)
count
800
600
400
200
0
0
20
40
polar angle (deg)


cam0: azimuthal error
reprojection error (pixels)
1.2
1.0
0.8
0.6
0.4
0.2
0.0
−100
0
100
azimuthal angle (deg)
count
1200
1000
800
600
400
200
0
−100
0
100
azimuthal angle (deg)


cam0: reprojection errors
0
200
400
600
0
500
1000
error y (pix)
2.0
1.5
1.0
0.5
0.0
−0.5
−1.0
−1.5
−2.0
−1
0
1
error x (pix)
40
35
30
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