

Calibration results

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Camera-system parameters:

cam0 (/hikrobot_camera/rgb):

type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>

distortion: [0.32530059 0.35358815 -0.79365363 1.8973045] +- [0.00706656 0.13025656 0.94060052 2.28718017]

projection: [4819.64284965 4819.61229209 2044.91012858 1535.29662029] +- [3.30841712 3.24588855 1.00128757 1.0981787]

reprojection error: [-0.000002, -0.000003] +- [0.567882, 0.375692]

Target configuration

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Type: aprilgrid

Tags:

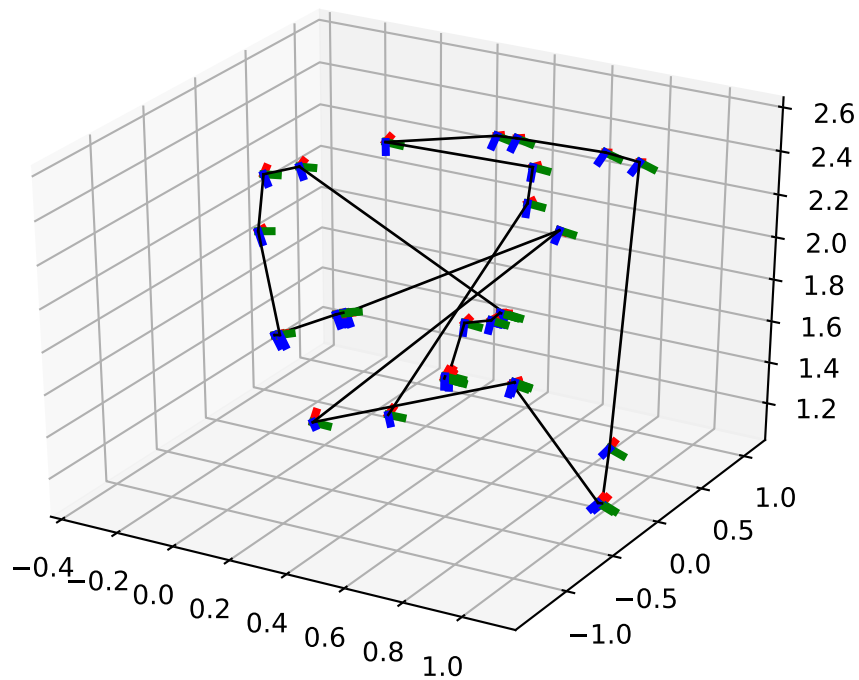
Rows: 6

Cols: 6

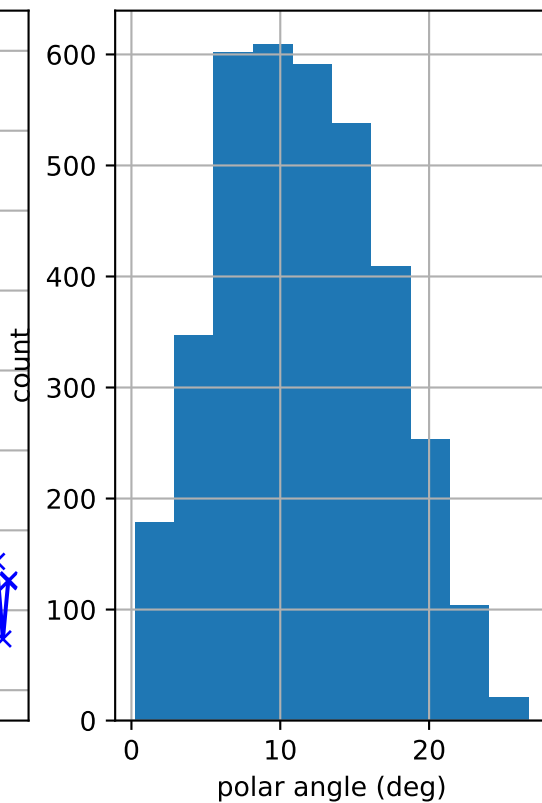
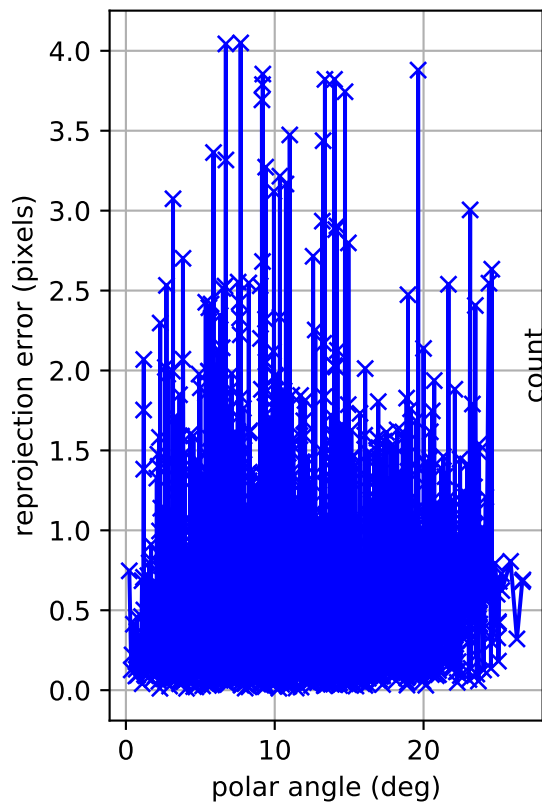
Size: 0.088 [m]

Spacing 0.026399999999999996 [m]

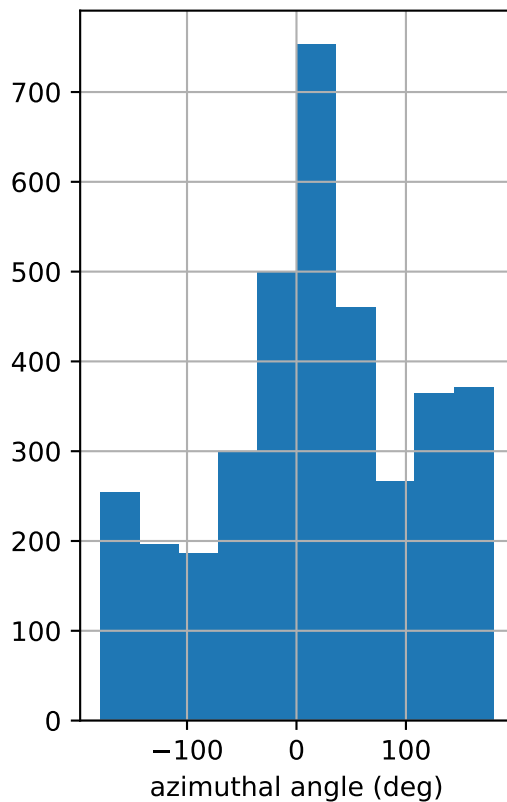
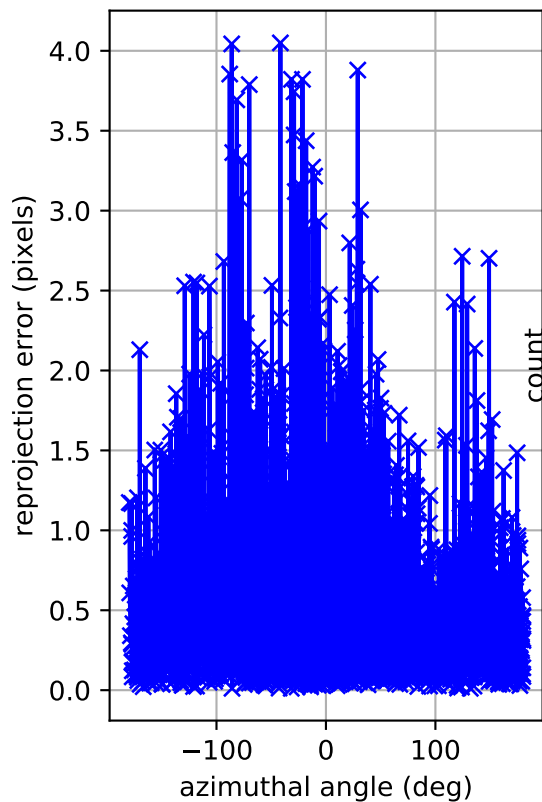
cam0: estimated poses



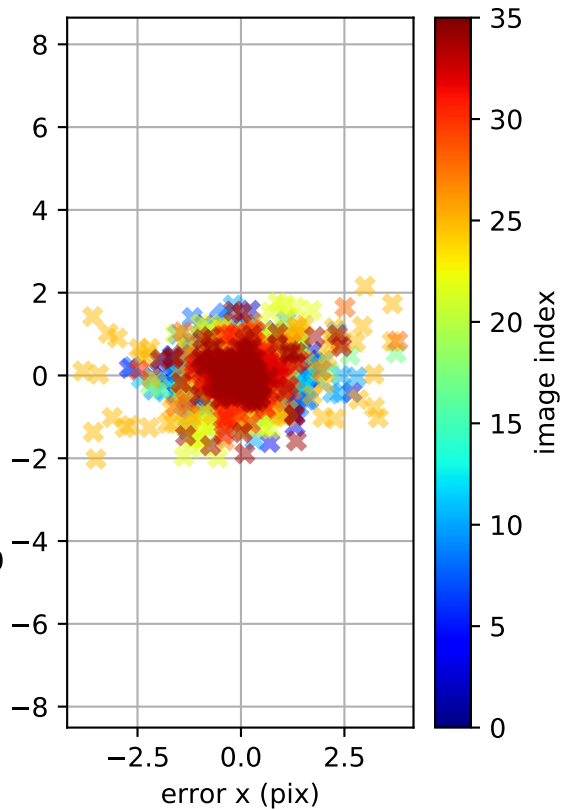
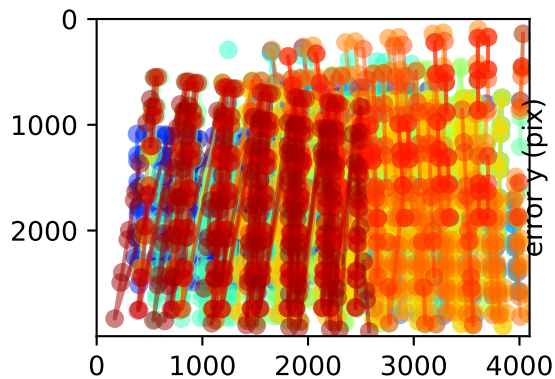
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

