

Calibration results

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Camera-system parameters:

cam0 (/capture_node/camera/image):

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

distortion: [-0.38176694 0.14885486 0.00003701 -0.00017057] +- [0.01533505 0.01458062 0.0021129 0.00150436]

projection: [252.3789391 252.40414164 173.43863462 120.19819515] +- [6.87542991 6.73437623 2.76942627 3.72934855]

reprojection error: [0.000000, 0.000000] +- [0.077347, 0.064261]

Target configuration

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Type: checkerboard

Rows

Count: 8

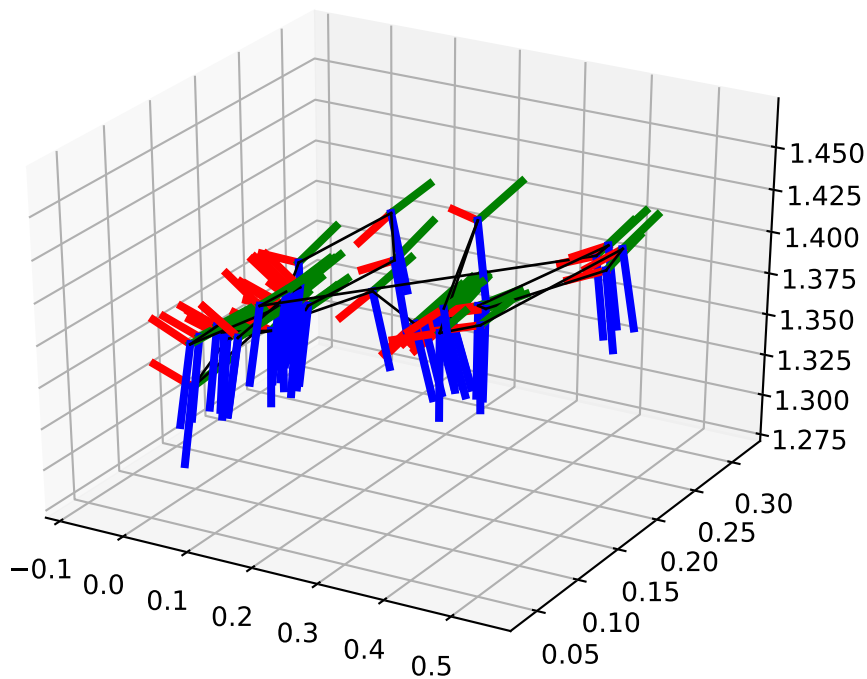
Distance: 0.06 [m]

Cols

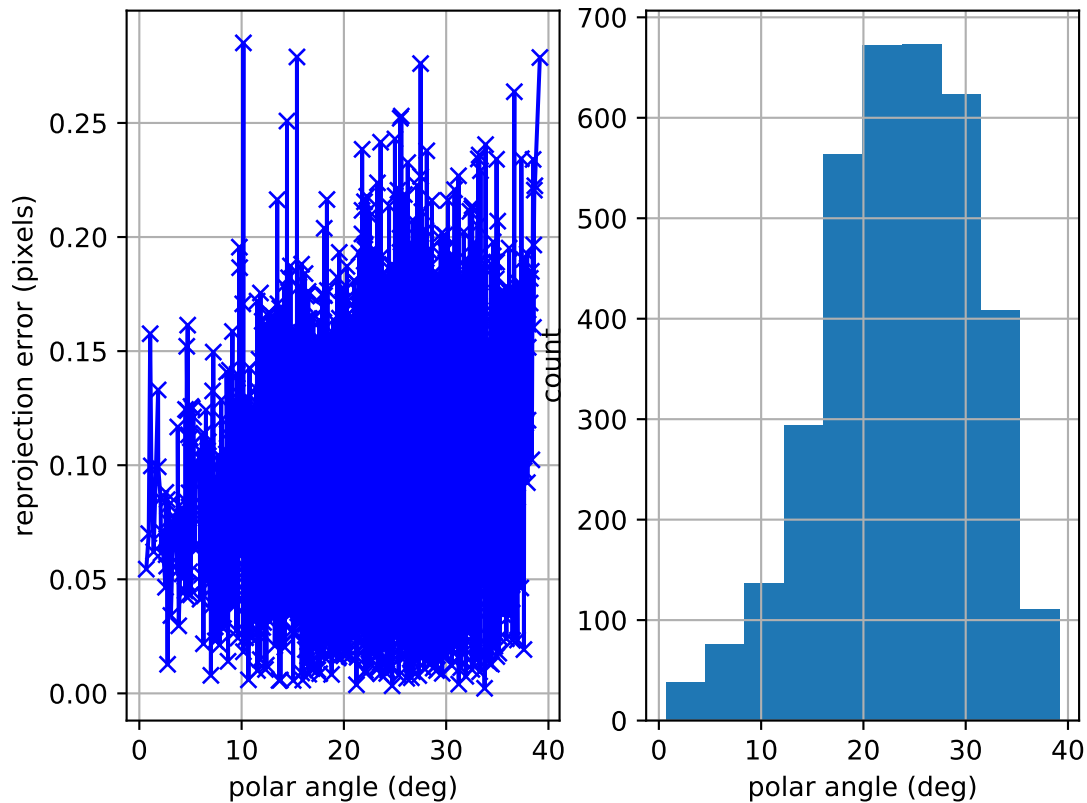
Count: 11

Distance: 0.06 [m]

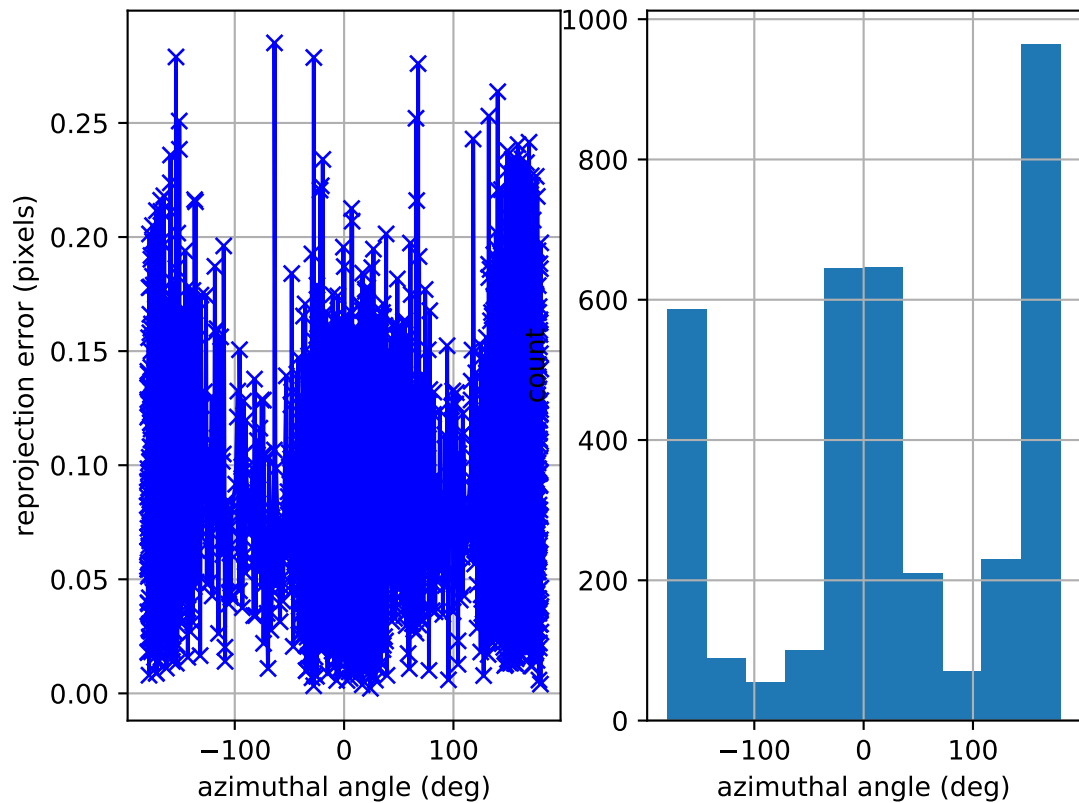
cam0: estimated poses



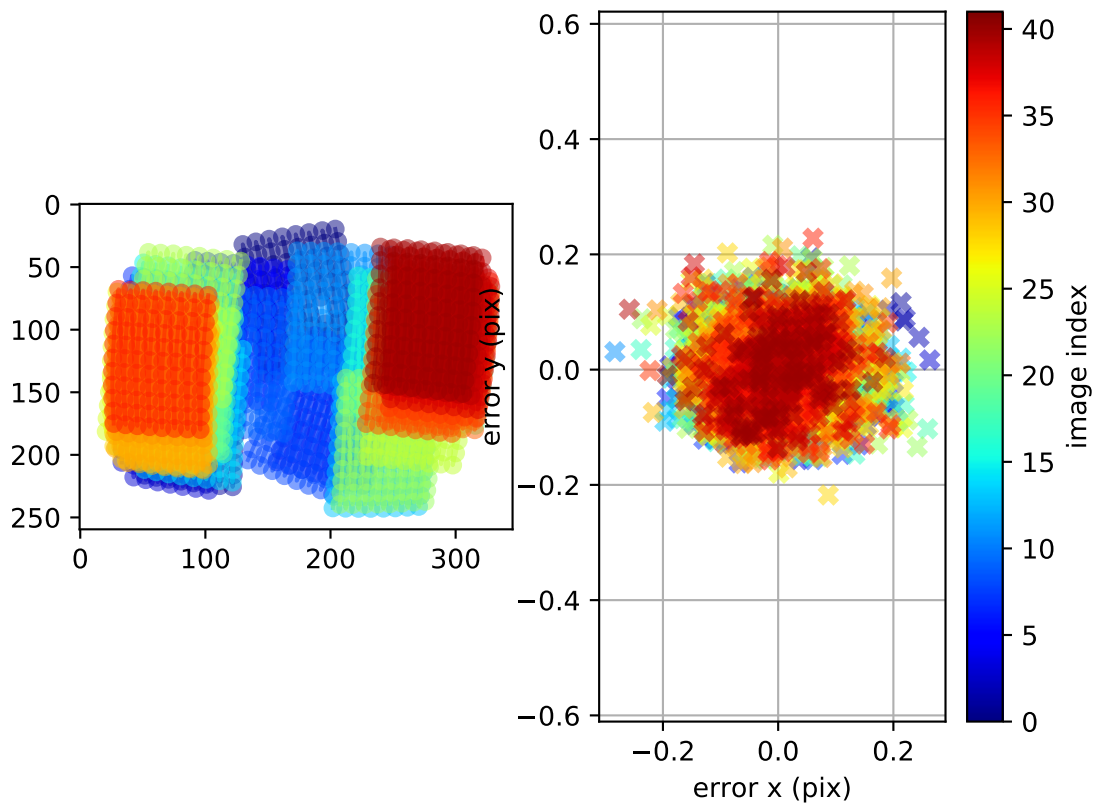
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

