

Calibration results

=====

Camera-system parameters:

cam0 (/stereo_camera/raw):

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

distortion: [0.41241755 -2.14893386 12.98859406 -22.24839029] +- [0.04046376 0.53667099 2.88515753 5.20241234]

projection: [500.32414335 500.40247593 311.14957496 261.95543036] +- [2.45069689 2.46764782 0.95329279
1.3258393]

reprojection error: [-0.000003, -0.000002] +- [0.384758, 0.319942]

Target configuration

=====

Type: aprilgrid

Tags:

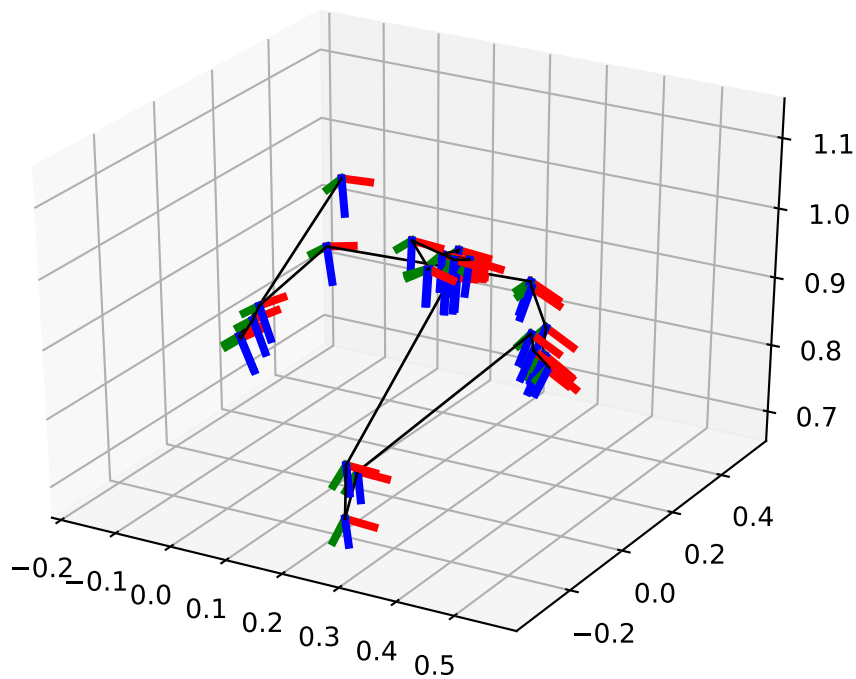
Rows: 6

Cols: 6

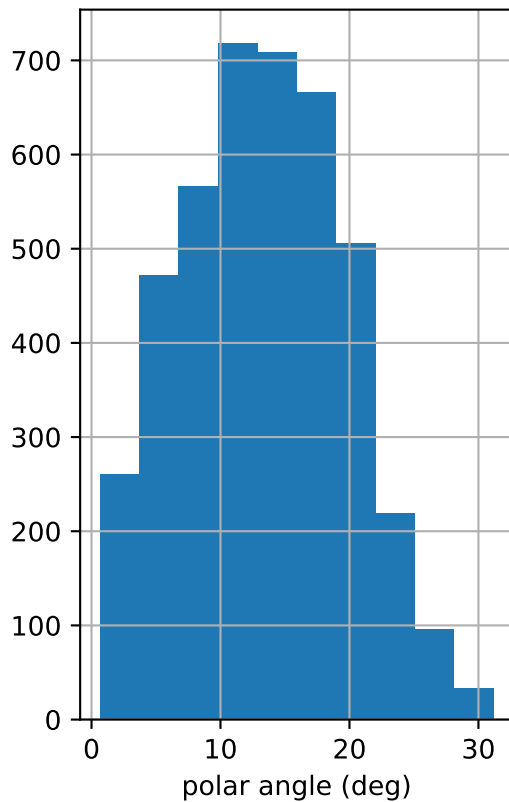
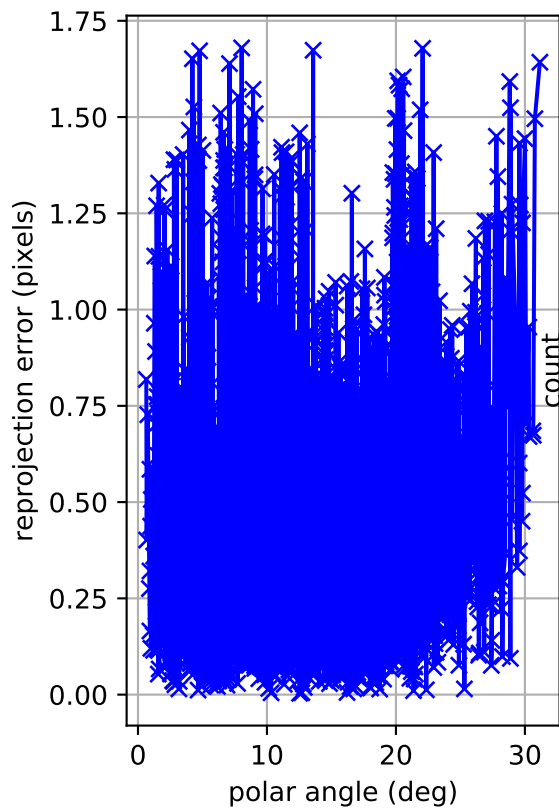
Size: 0.055 [m]

Spacing 0.016555 [m]

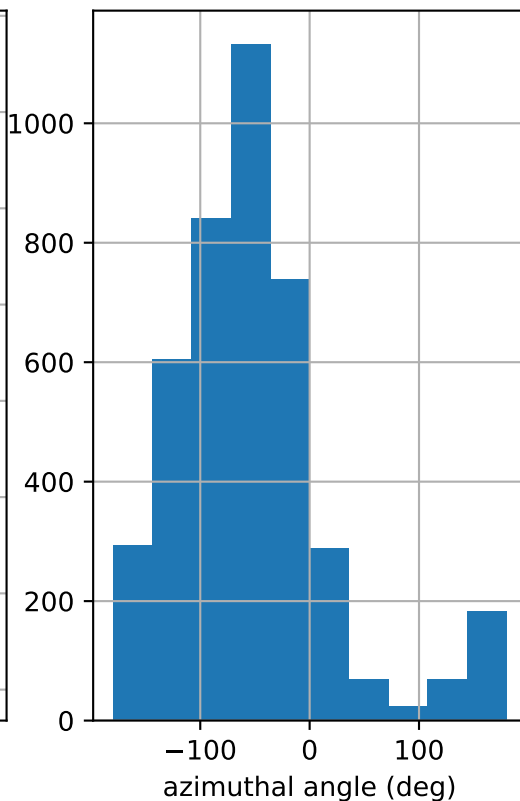
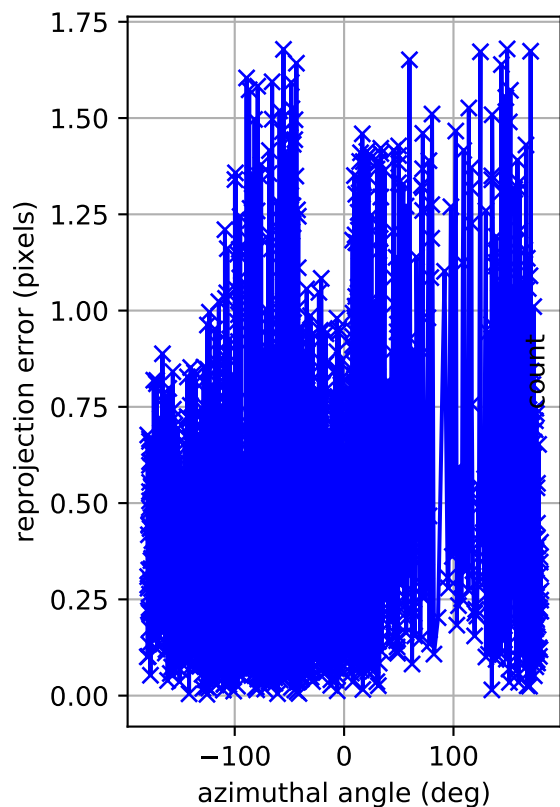
cam0: estimated poses



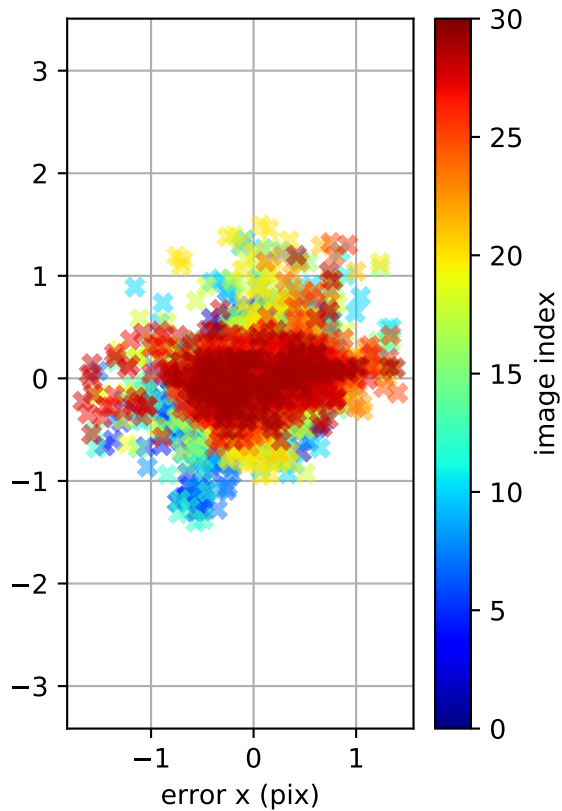
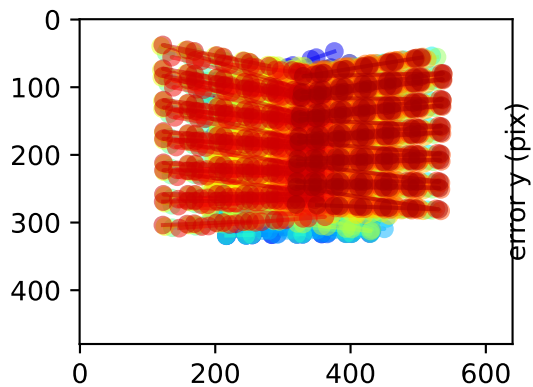
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

