

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.04495678 -0.00446366 0.00659666 -0.0056231] +- [0.00779511 0.02727364 0.03856171 0.01881667]

projection: [387.85552645 389.22655764 645.20672687 371.60636812] +- [0.7288683 0.75899787 0.56084779
1.00351969]

reprojection error: [-0.000001, 0.000000] +- [0.244293, 0.232750]

Target configuration

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Type: aprilgrid

Tags:

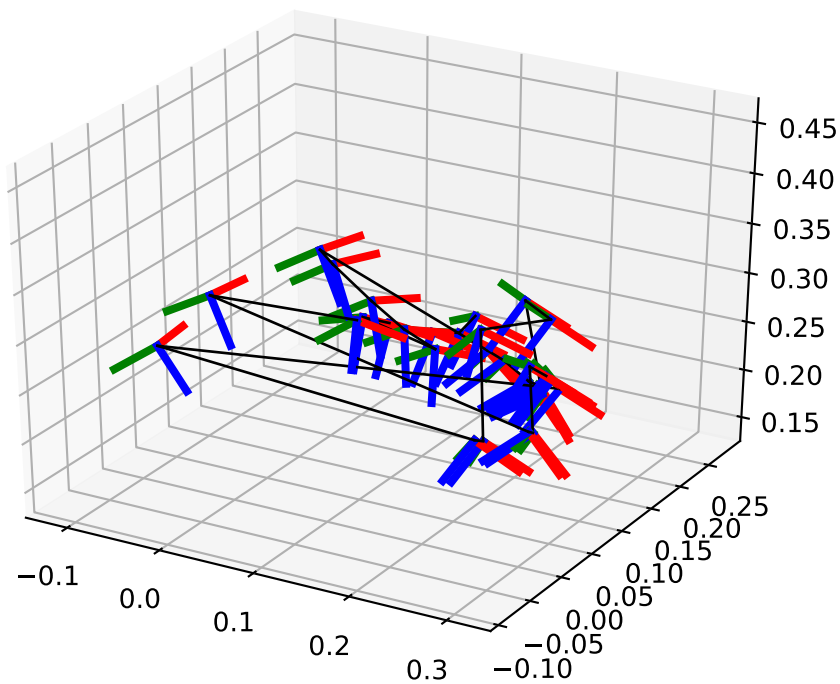
Rows: 8

Cols: 6

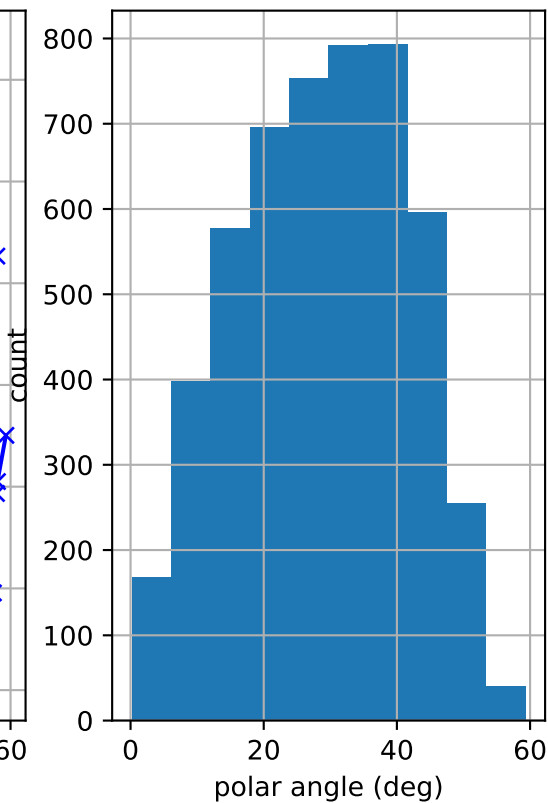
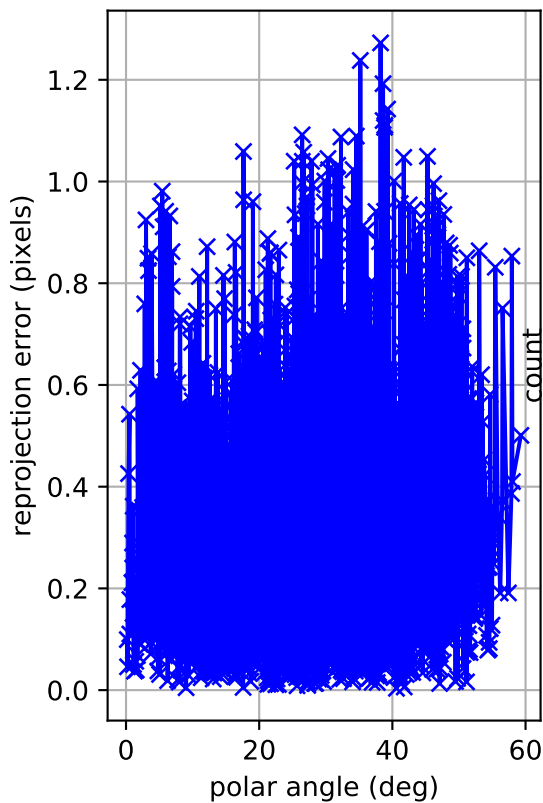
Size: 0.023 [m]

Spacing 0.0069 [m]

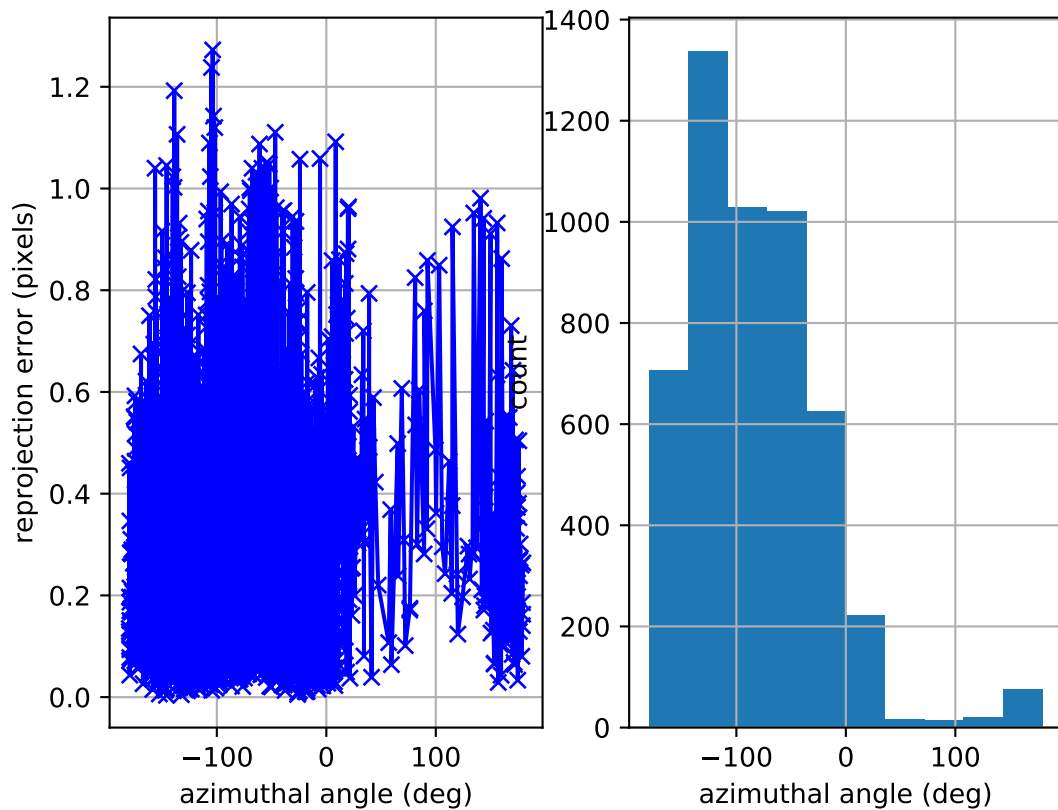
cam0: estimated poses



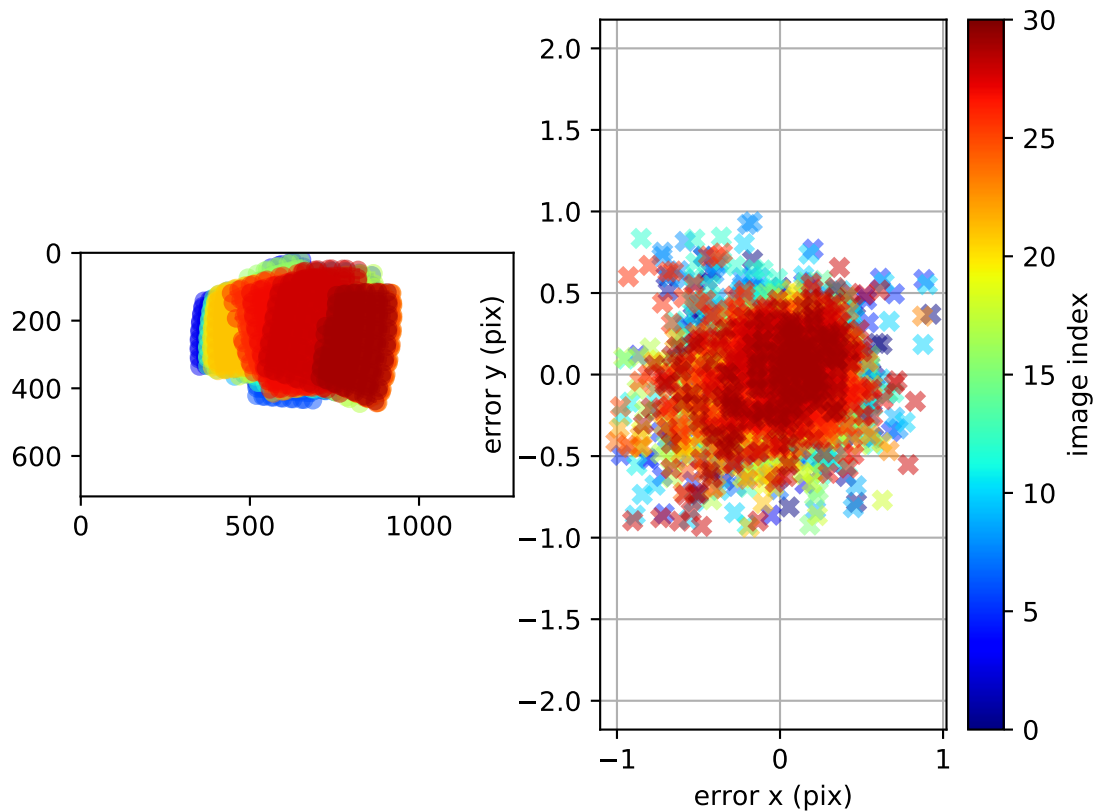
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

