

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18779765 0.02143592 -0.00664867 0.00239832] +- [0.00624979 0.01941118 0.02297603 0.00912819]

projection: [336.4600678 336.5976214 394.41040204 299.85036674] +- [0.45815146 0.51987309 0.16815481
0.19055208]

reprojection error: [0.000003, 0.000000] +- [0.156170, 0.149947]

Target configuration

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Type: aprilgrid

Tags:

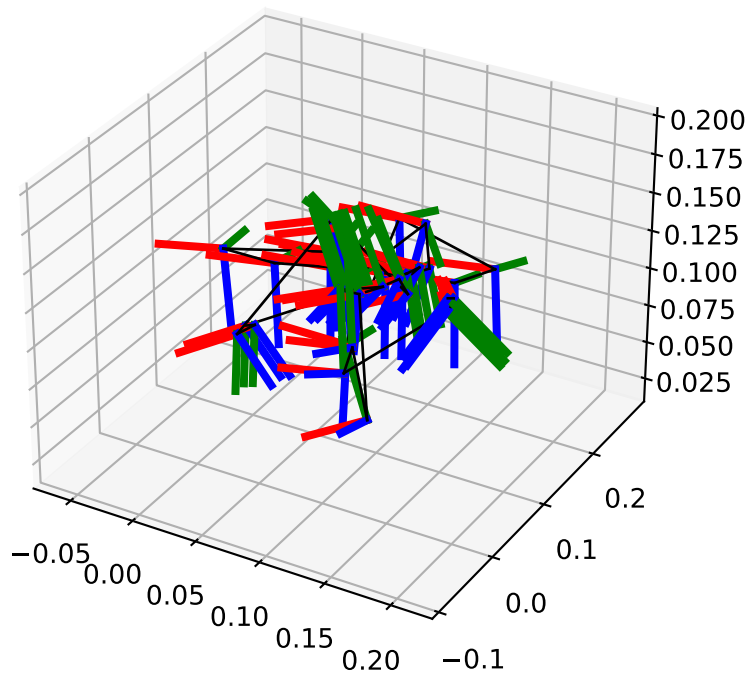
Rows: 6

Cols: 6

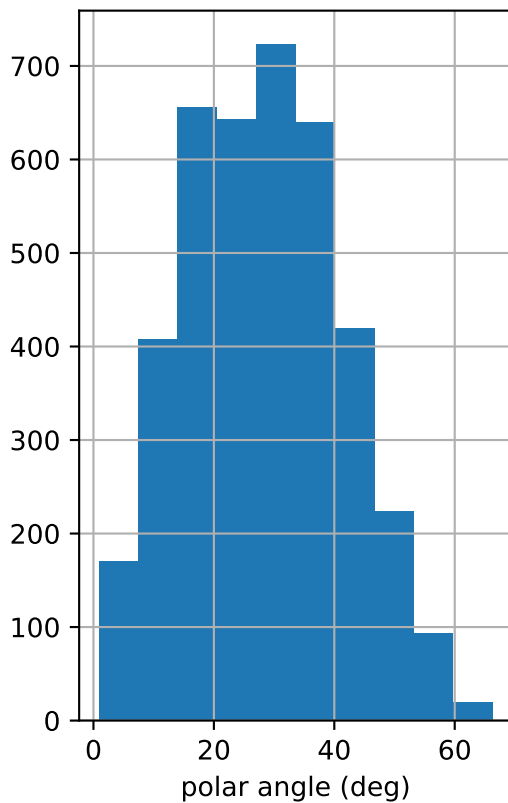
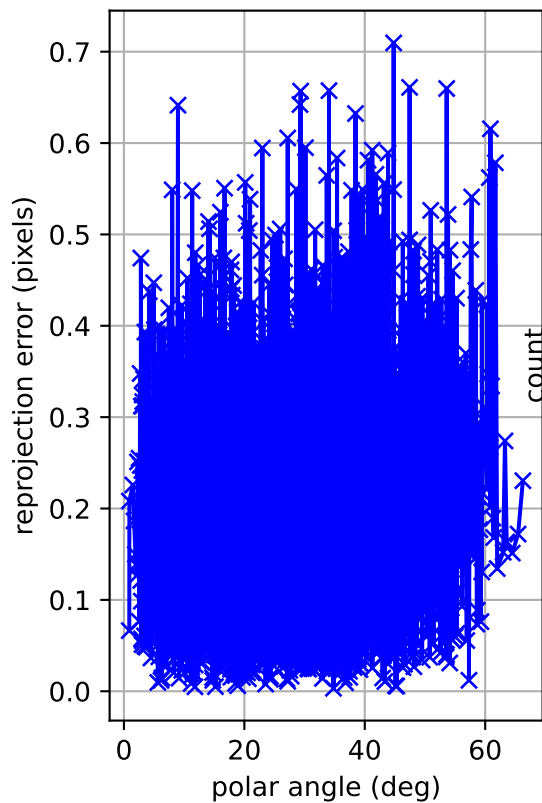
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

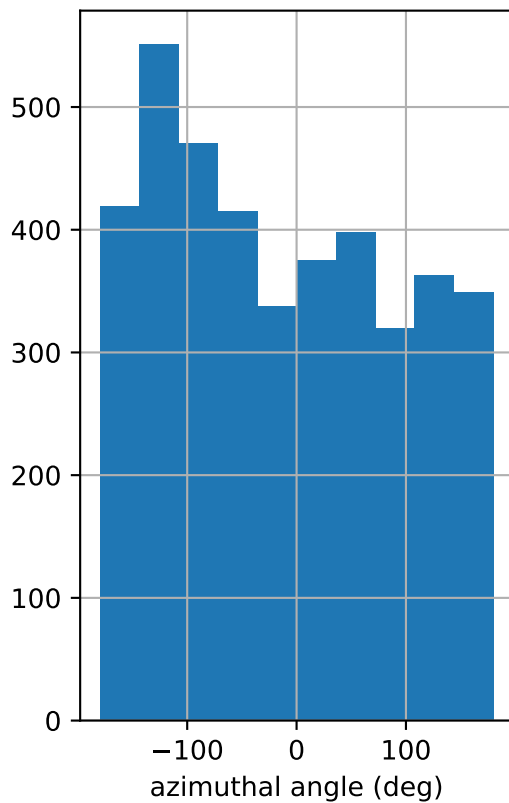
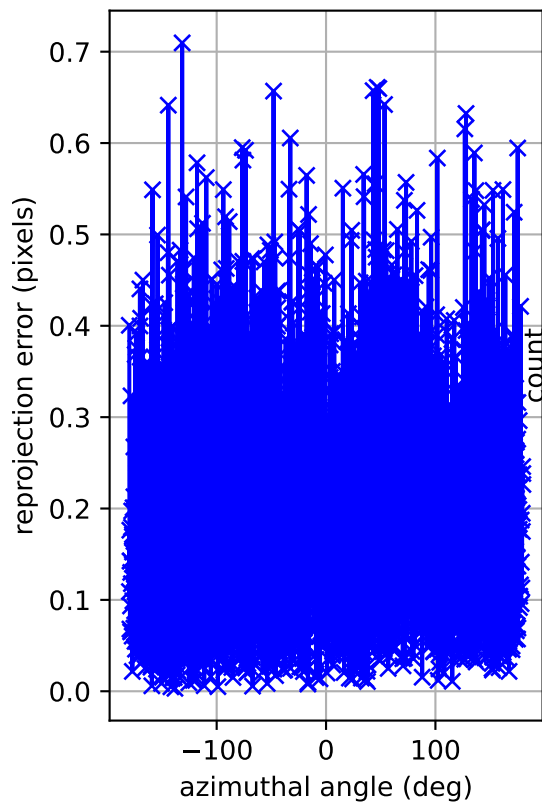
cam0: estimated poses



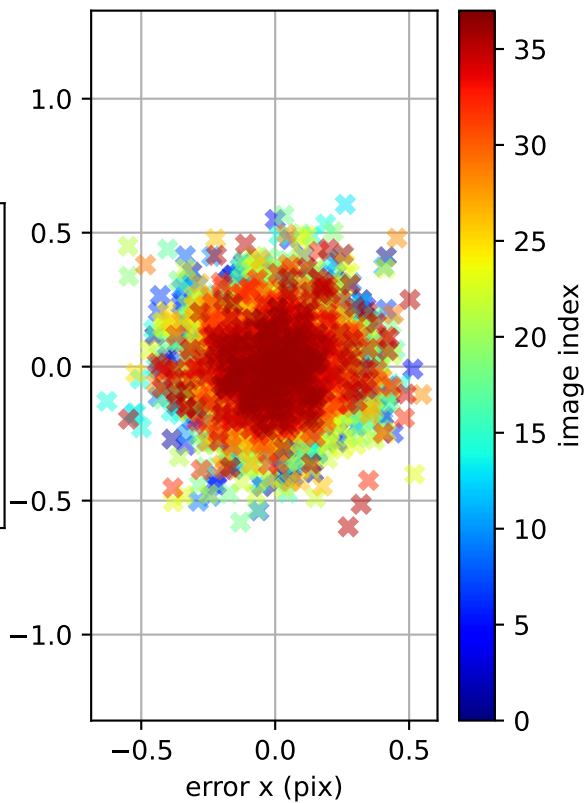
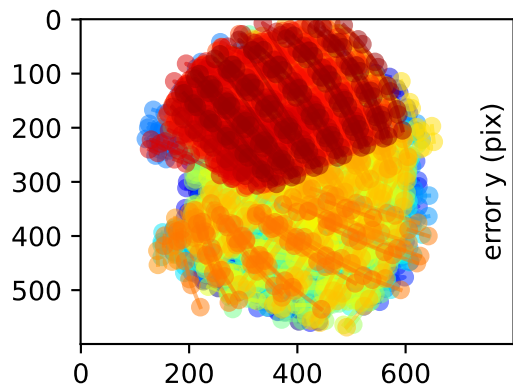
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

