

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18371823 0.02166855 -0.00880712 0.00332659] +- [0.00555929 0.01658326 0.01900966 0.00727764]

projection: [432.16449664 432.31894174 531.09160169 390.07632918] +- [0.51198855 0.57236539 0.18368912
0.22761243]

reprojection error: [-0.000004, 0.000000] +- [0.208890, 0.201709]

Target configuration

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Type: aprilgrid

Tags:

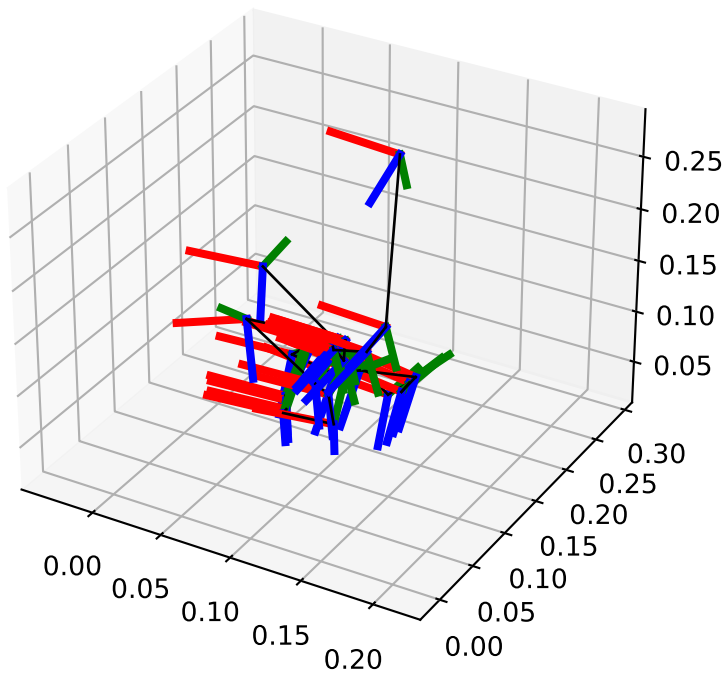
Rows: 6

Cols: 6

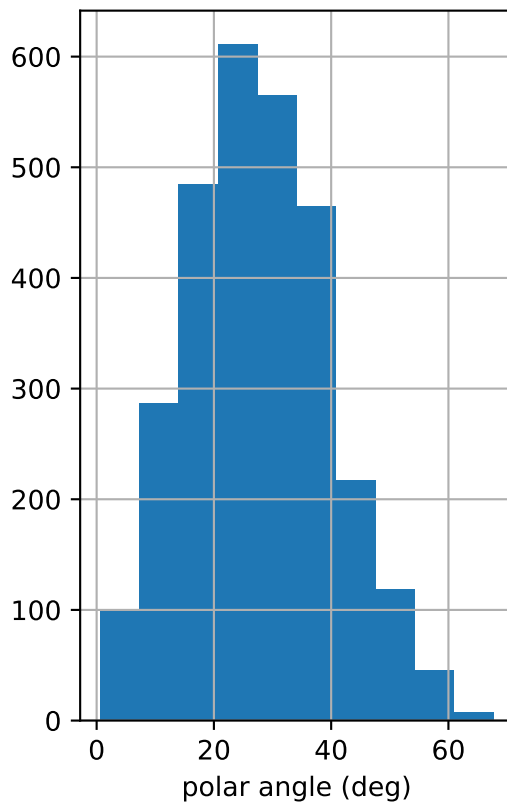
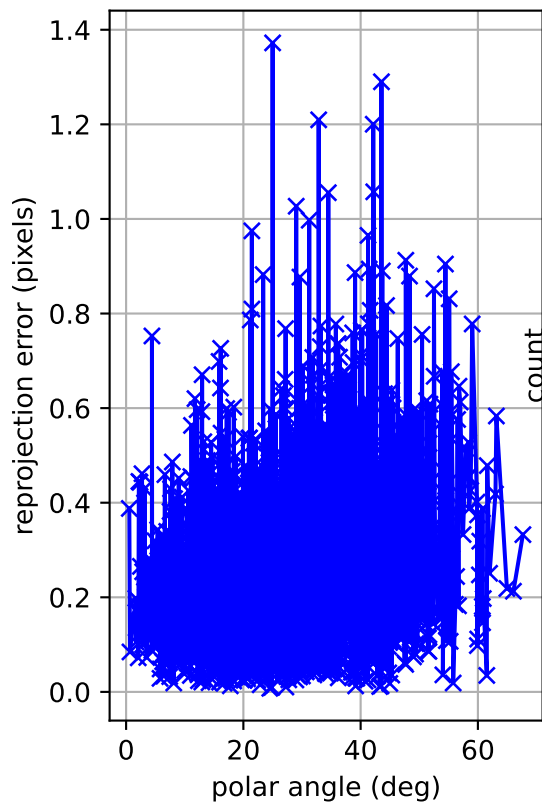
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

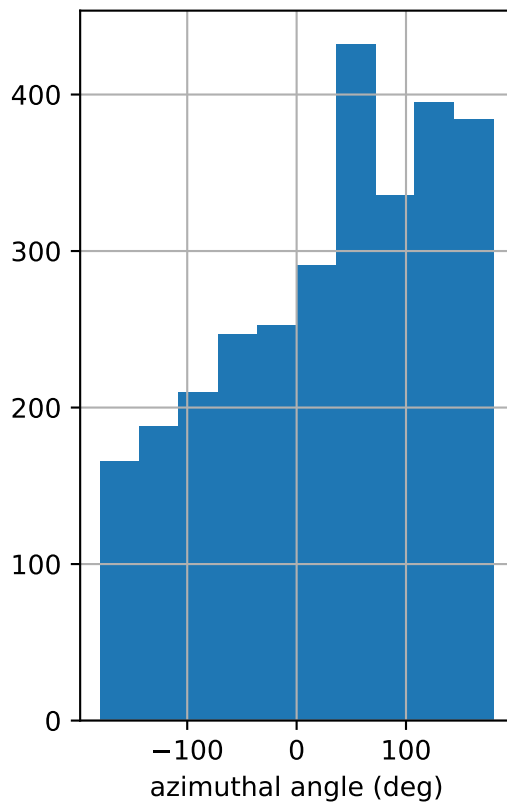
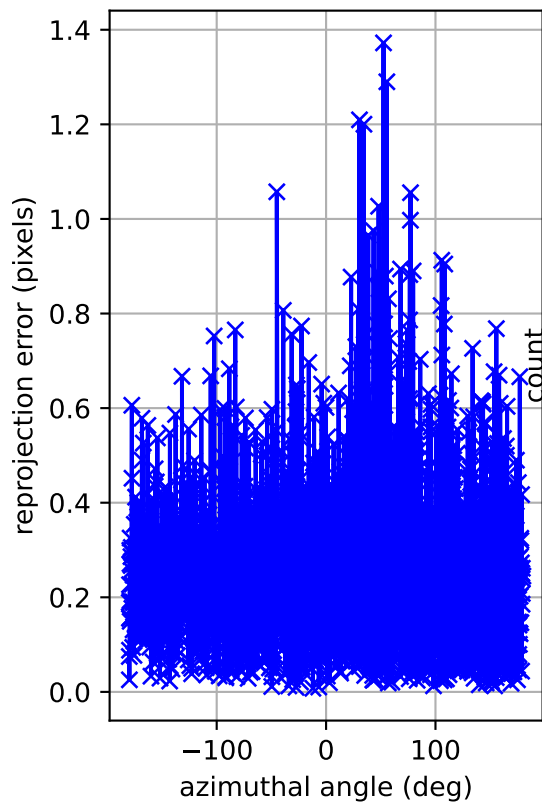
cam0: estimated poses



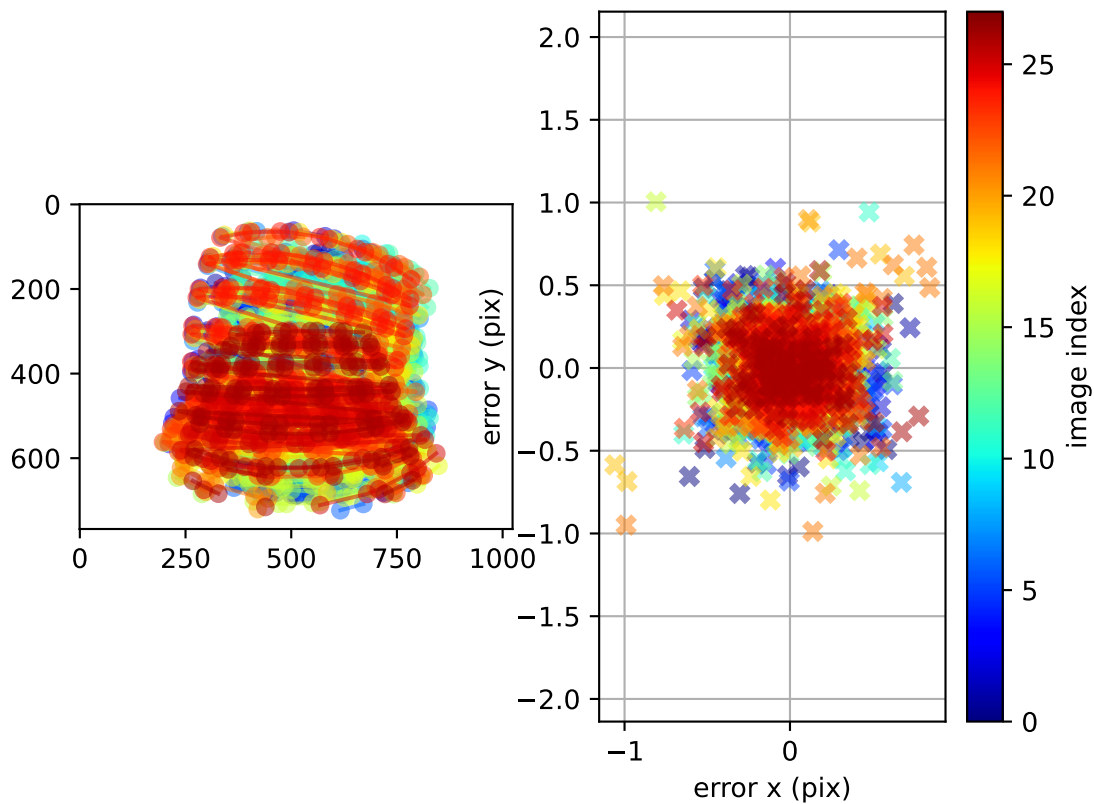
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

