

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18569495 0.02147269 -0.00604777 0.00155318] +- [0.0030985 0.00809321 0.00824308 0.00283829]

projection: [601.25387146 601.47809585 947.19548123 538.87366327] +- [0.48898224 0.52662579 0.17210053
0.30154823]

reprojection error: [-0.000019, 0.000007] +- [0.647515, 0.559521]

Target configuration

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Type: aprilgrid

Tags:

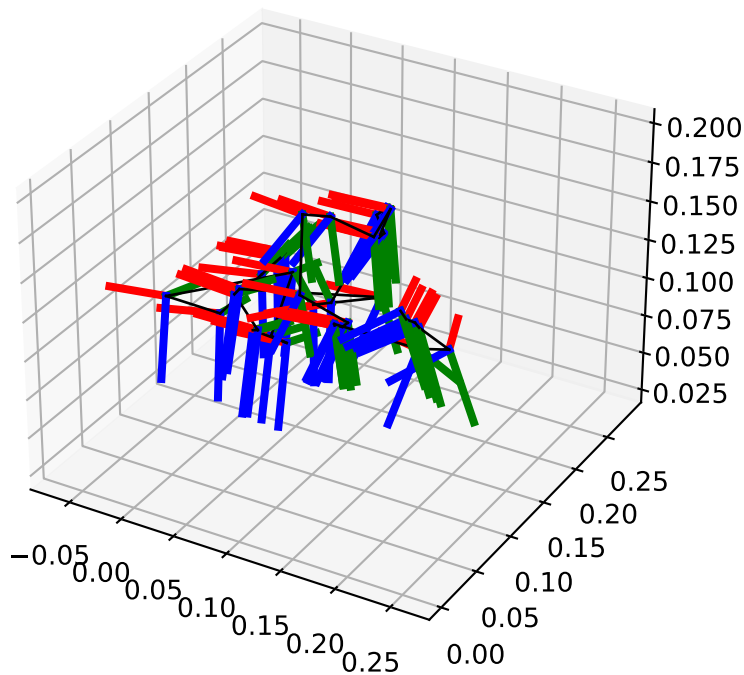
Rows: 6

Cols: 6

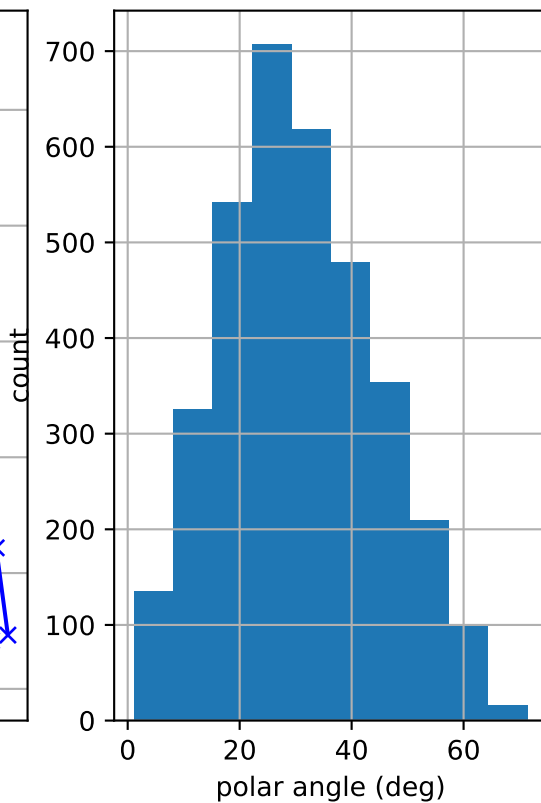
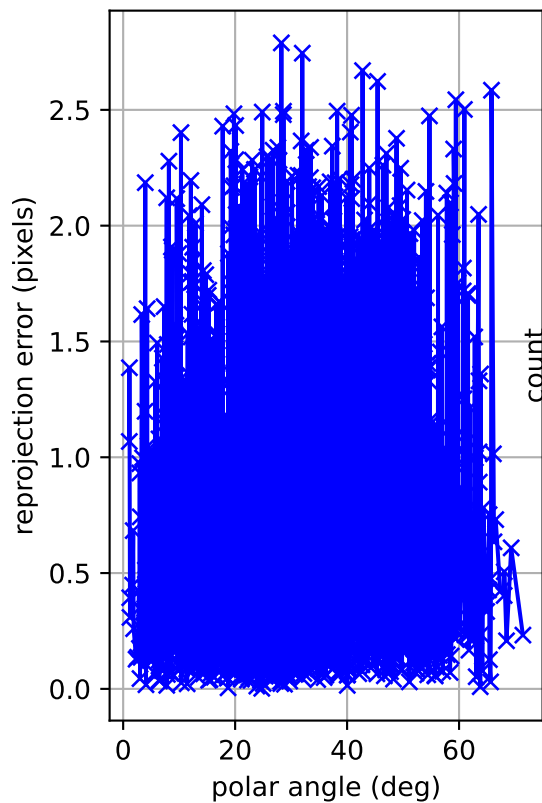
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

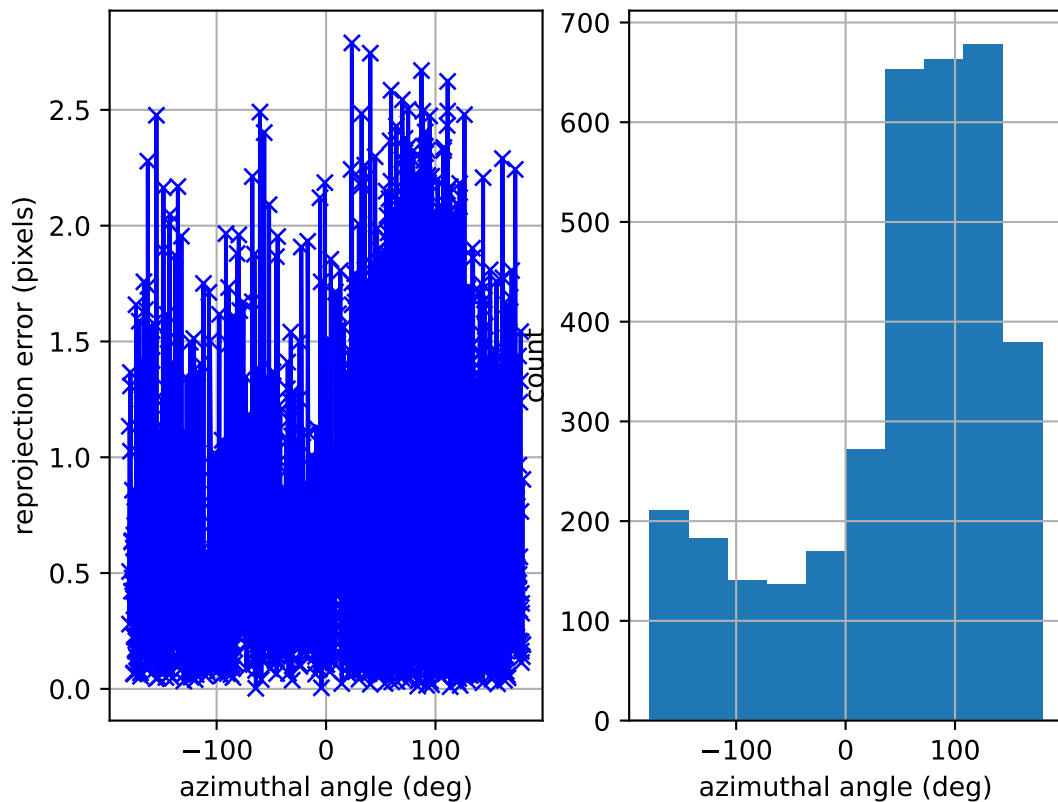
cam0: estimated poses



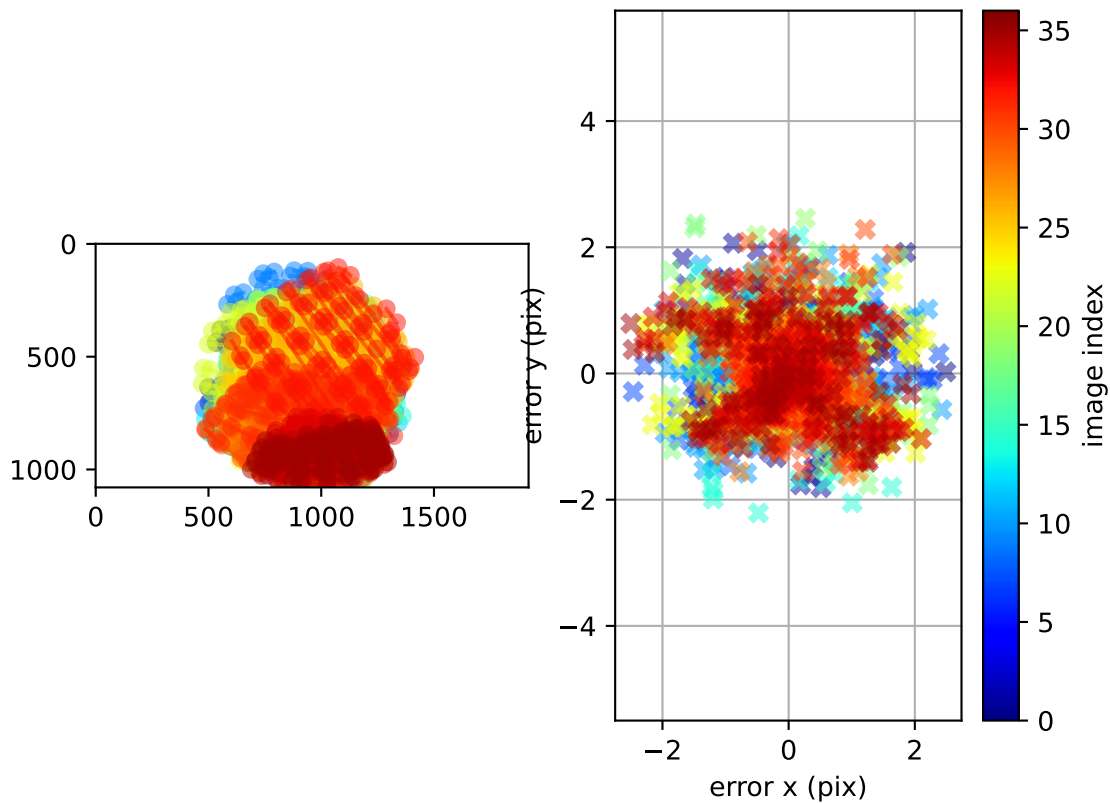
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

