

## Calibration results

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### Camera-system parameters:

cam0 (/usb\_cam/image\_raw):

type: <class 'aslam\_cv.libaslam\_cv\_python.EquidistantDistortedPinholeCameraGeometry'>

distortion: [-0.18488207 0.01849904 -0.00569835 0.00181811] +- [0.00592992 0.01871595 0.02259631 0.00910073]

projection: [431.53516682 431.74765987 506.29101716 385.42169954] +- [0.55197252 0.57873863 0.22298451  
0.28377664]

reprojection error: [-0.000004, -0.000003] +- [0.204182, 0.189872]

## Target configuration

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Type: aprilgrid

Tags:

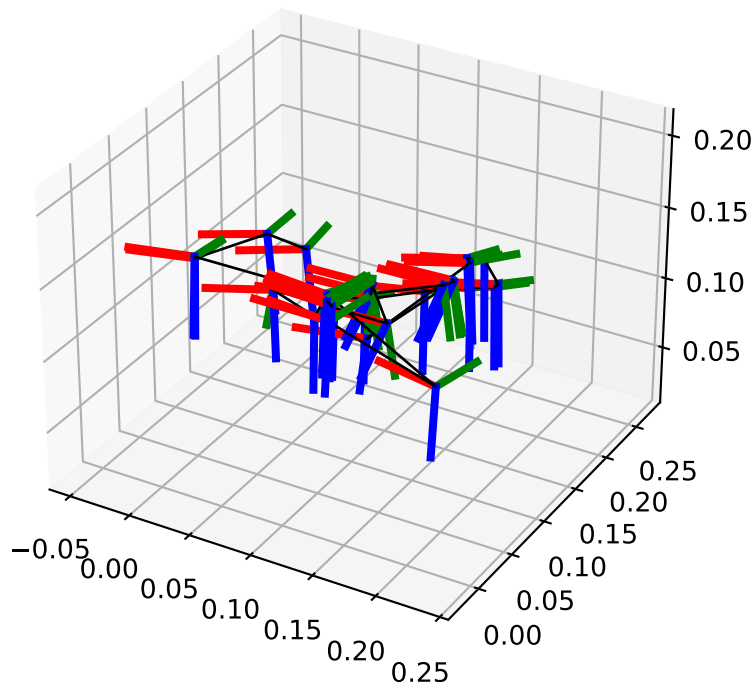
Rows: 6

Cols: 6

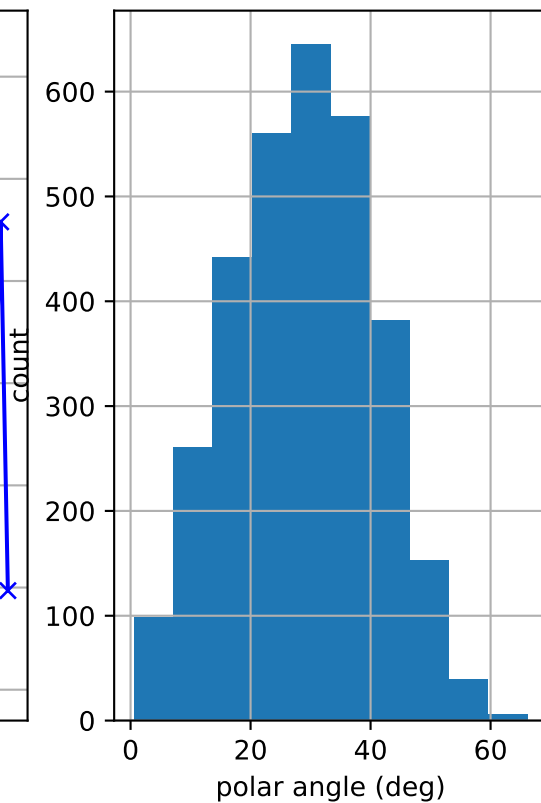
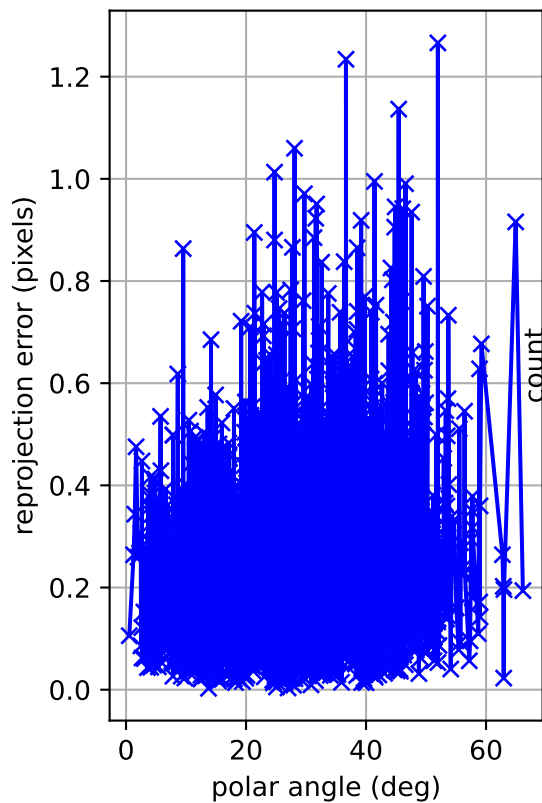
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

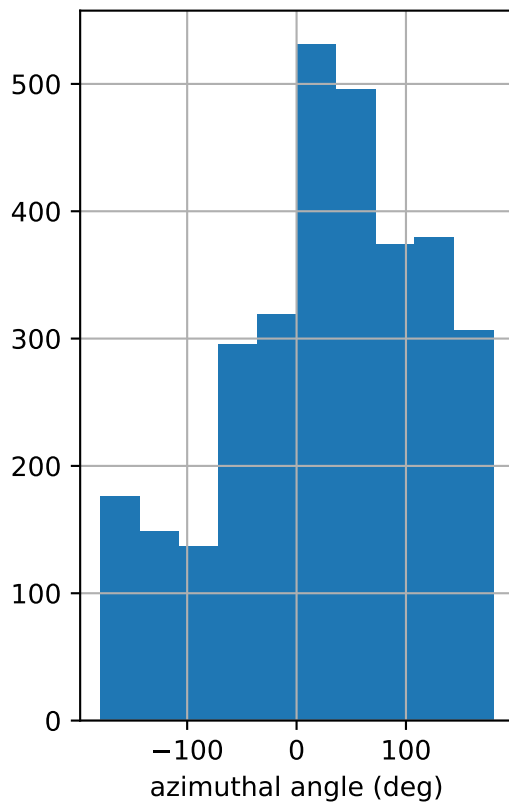
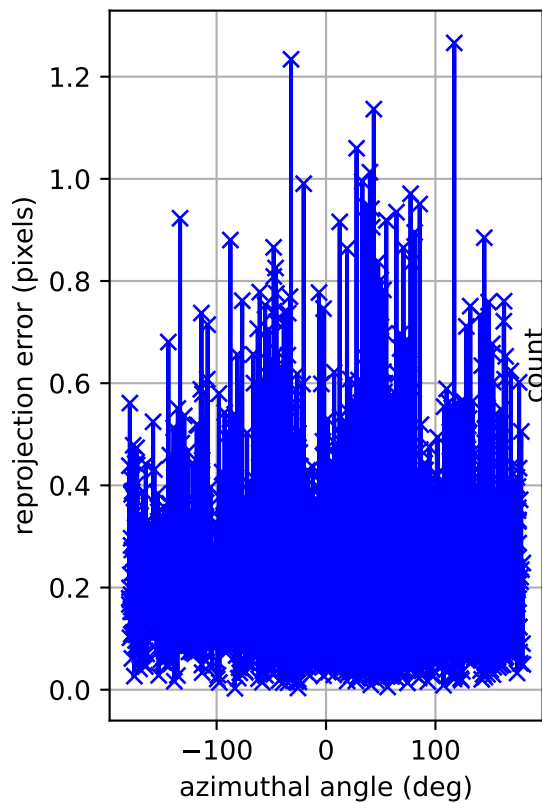
cam0: estimated poses



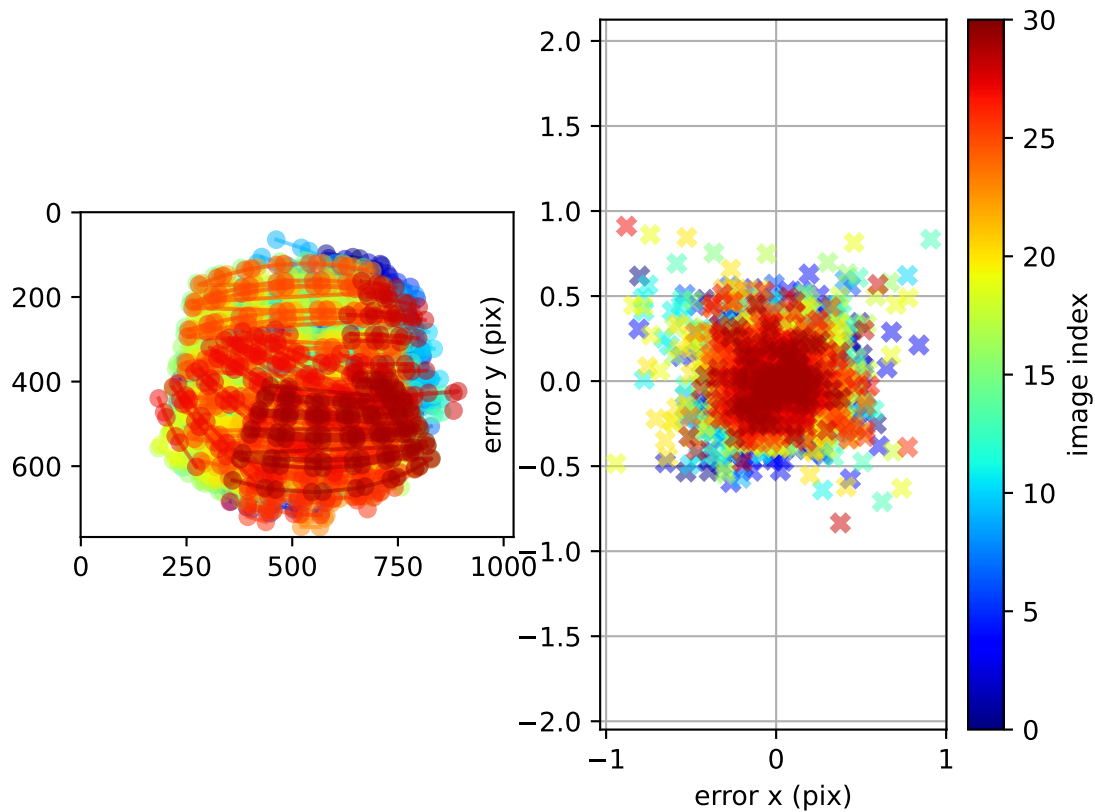
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



# Location of removed outlier corners

cam0

