

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18736821 0.02460242 -0.00806782 0.00205066] +- [0.00305777 0.00781467 0.00765521 0.00251502]

projection: [573.47624531 574.16426361 662.3789755 516.21699372] +- [0.46095458 0.50592761 0.18954762
0.31325578]

reprojection error: [0.000000, 0.000000] +- [0.416648, 0.425538]

Target configuration

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Type: aprilgrid

Tags:

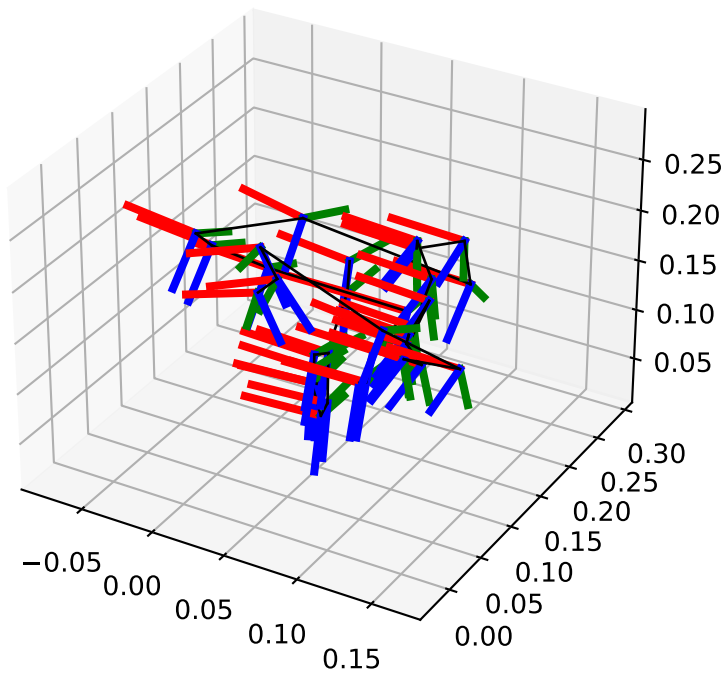
Rows: 6

Cols: 6

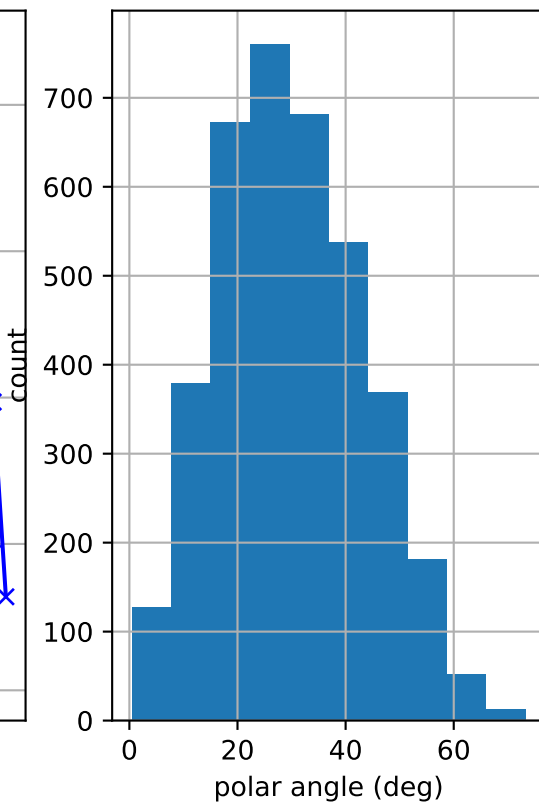
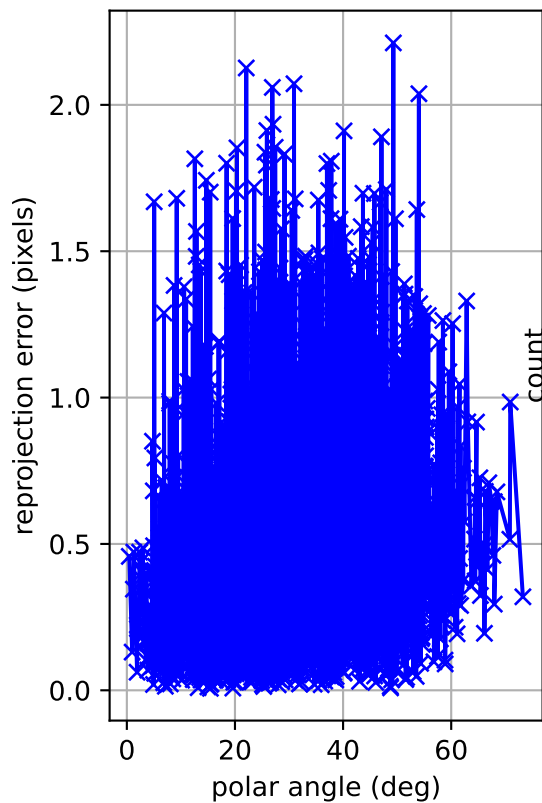
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

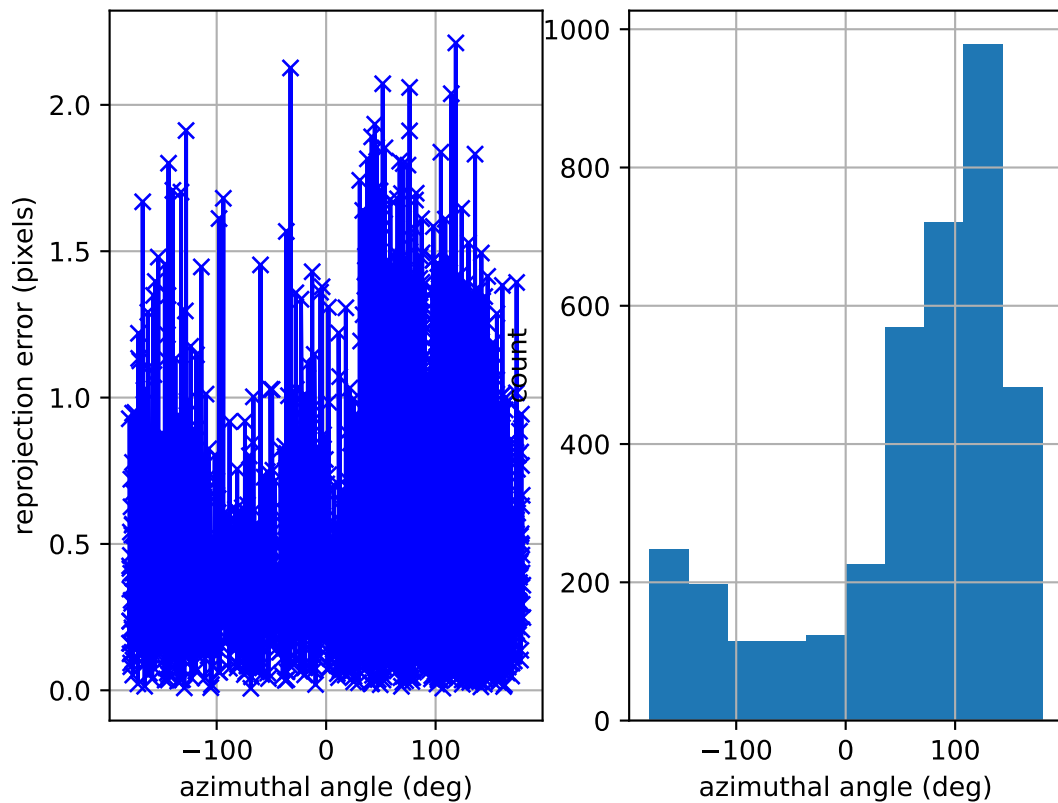
cam0: estimated poses



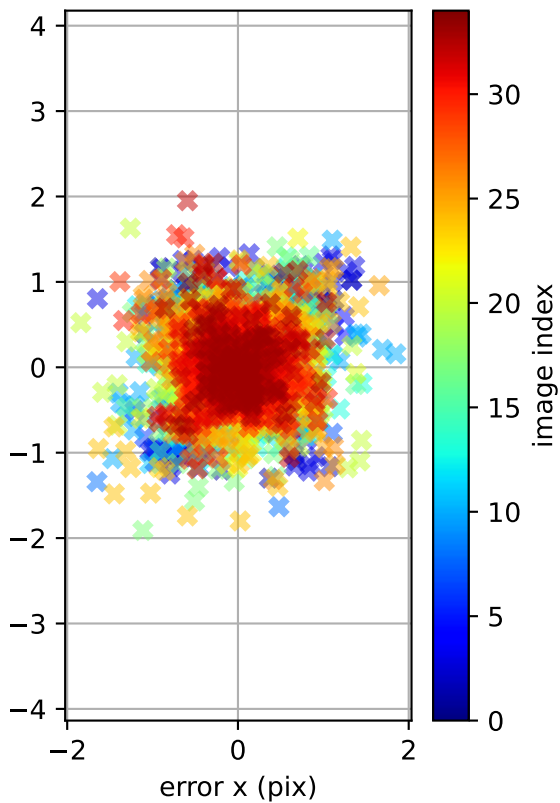
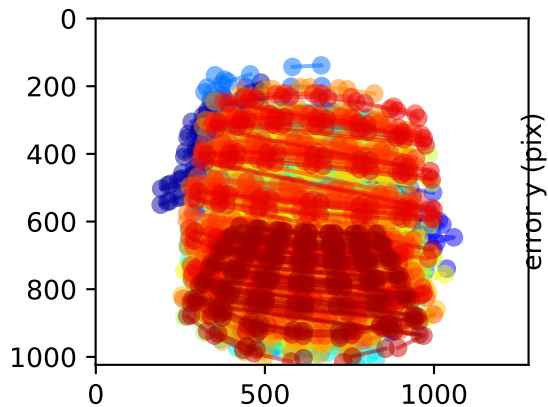
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

