

Calibration results

=====

Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18751157 0.02053236 -0.00487739 0.00142365] +- [0.00523181 0.01246973 0.01143722 0.00355897]

projection: [338.19989517 338.26219332 425.89639986 298.59846823] +- [0.42054508 0.45479702 0.16434078
0.18091999]

reprojection error: [-0.000002, 0.000002] +- [0.150247, 0.155786]

Target configuration

=====

Type: aprilgrid

Tags:

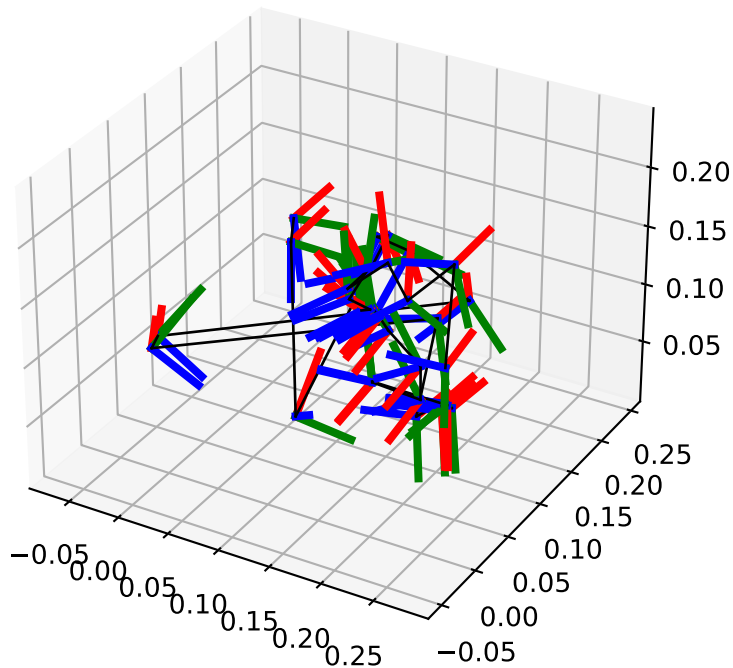
Rows: 6

Cols: 6

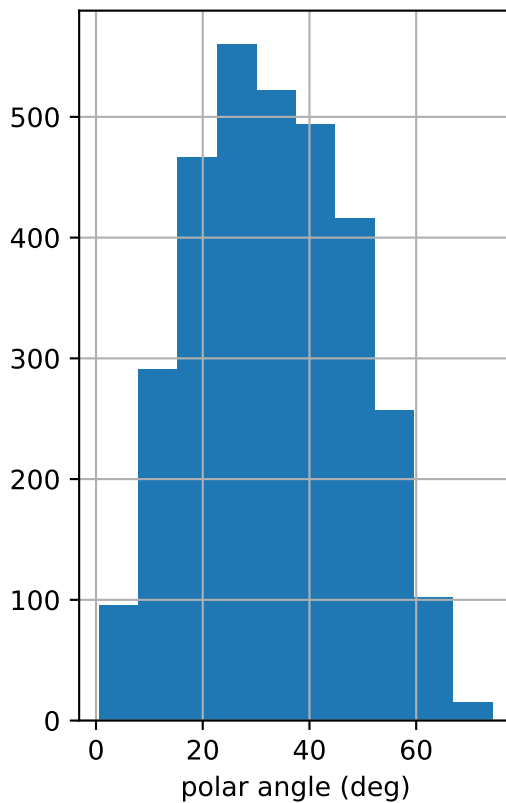
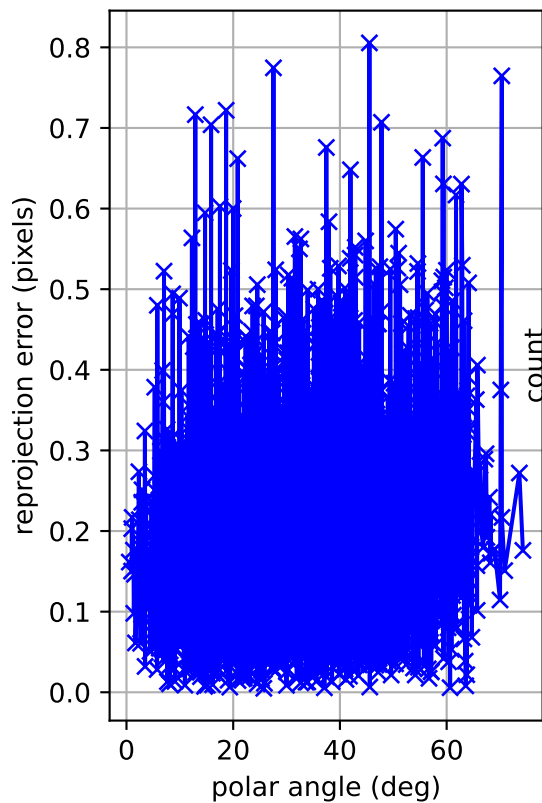
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

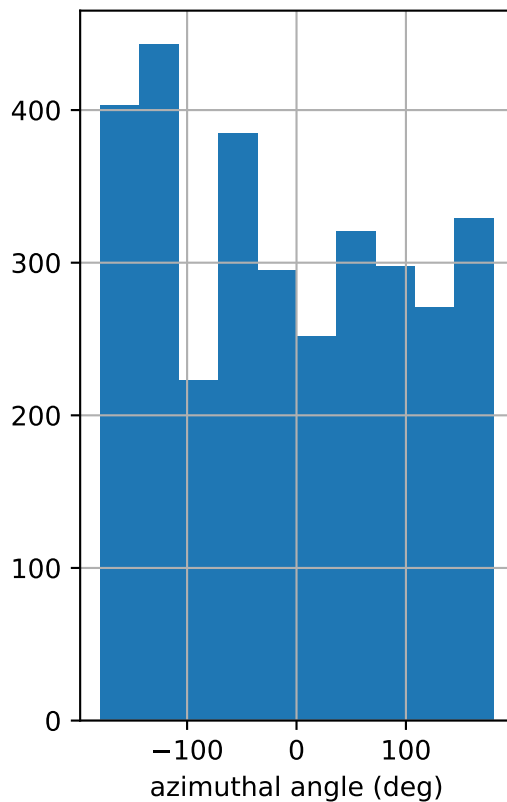
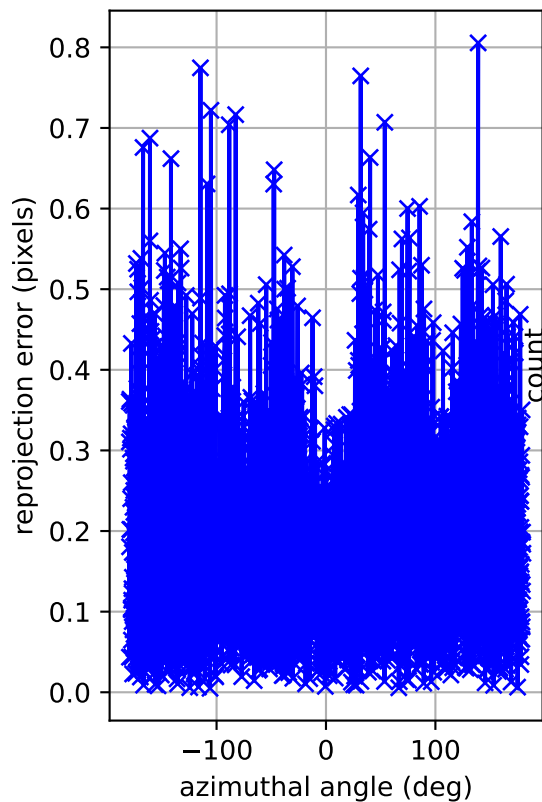
cam0: estimated poses



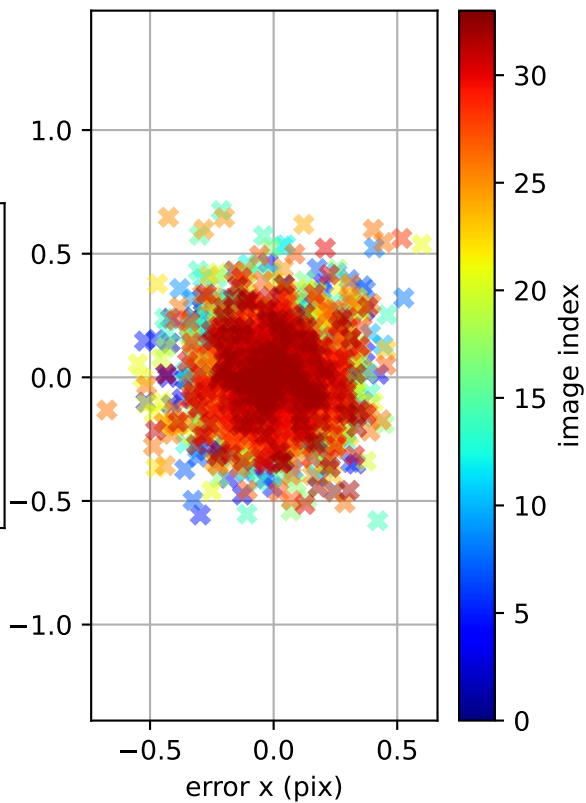
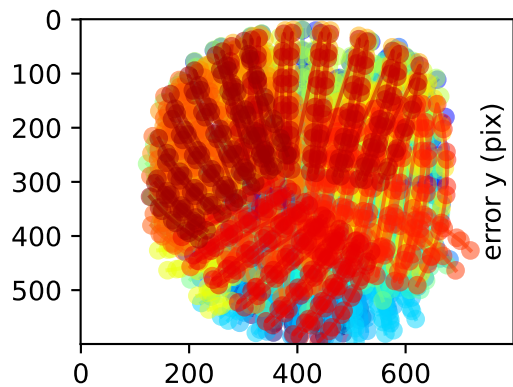
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

