

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18477394 0.01681783 -0.00168028 0.00073889] +- [0.0059869 0.01564359 0.01603765 0.00556459]

projection: [336.9060407 337.33334106 413.55791313 303.05522932] +- [0.51063828 0.550015 0.16032918
0.29122609]

reprojection error: [0.000007, 0.000000] +- [0.164662, 0.159792]

Target configuration

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Type: aprilgrid

Tags:

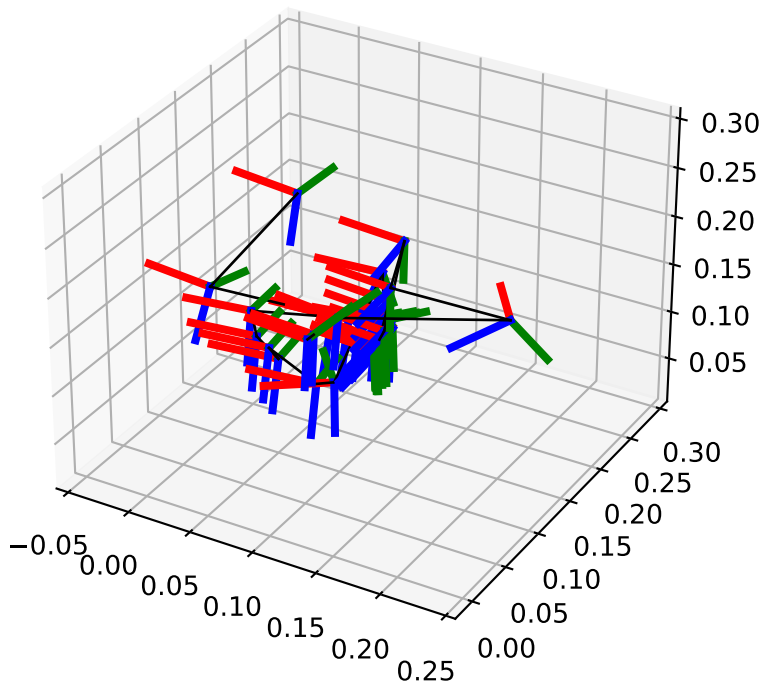
Rows: 6

Cols: 6

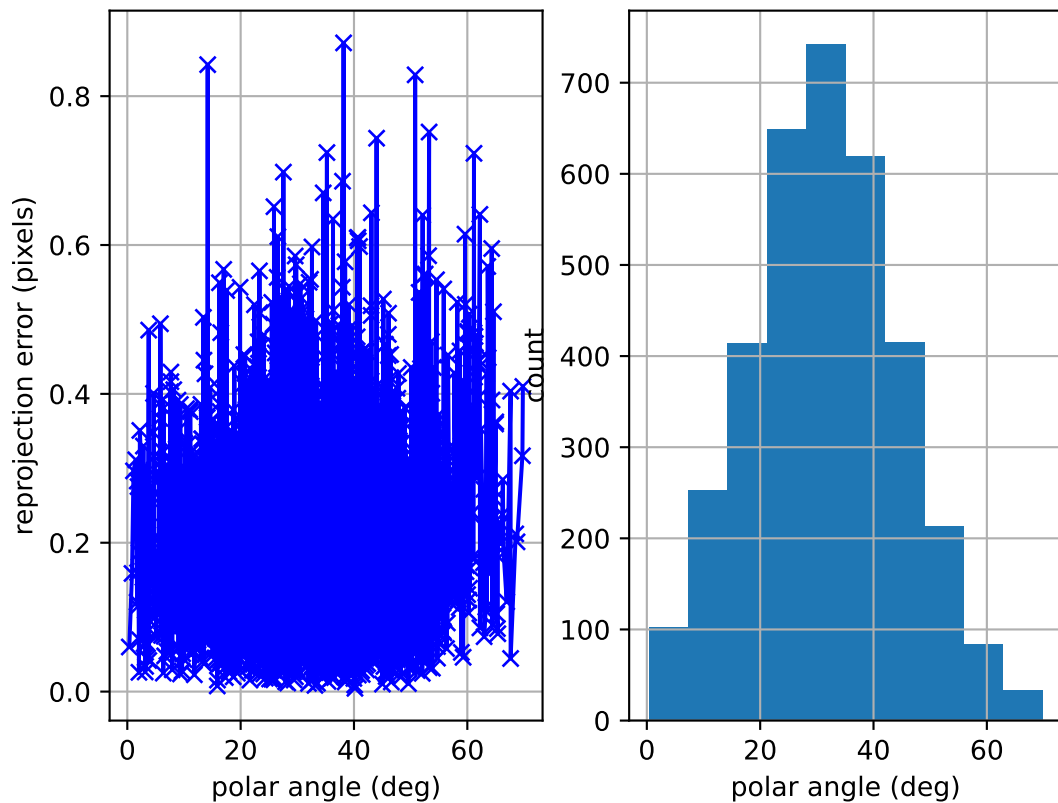
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

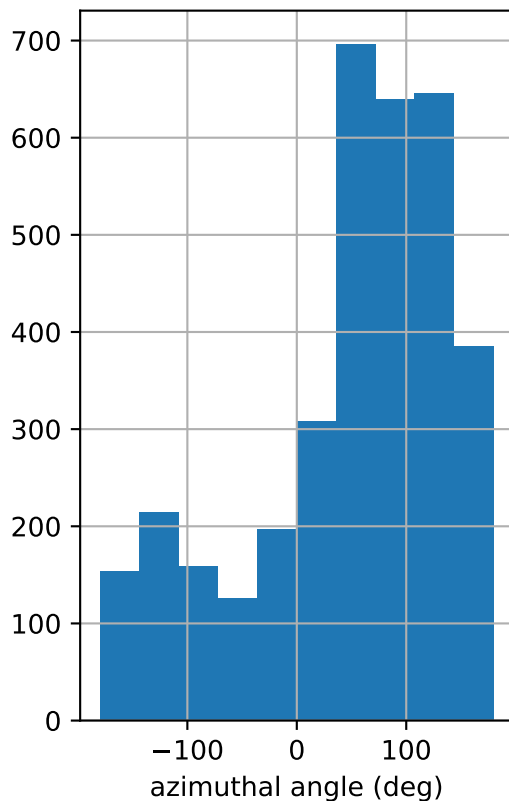
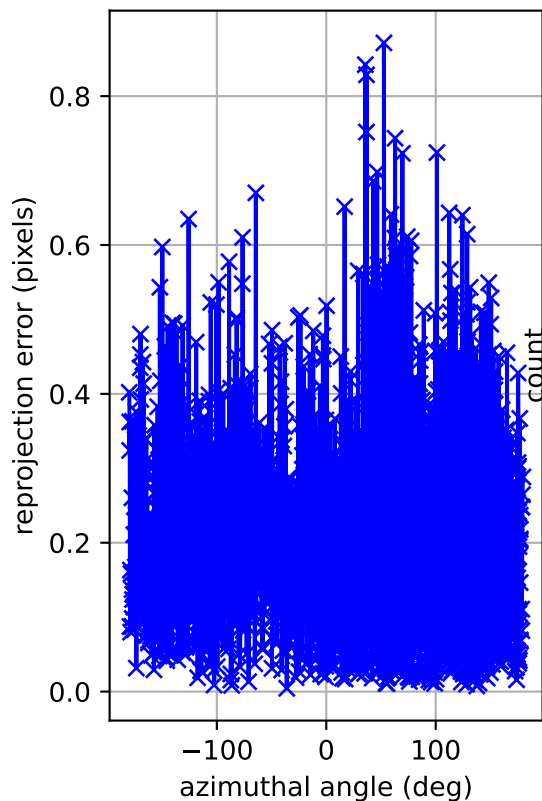
cam0: estimated poses



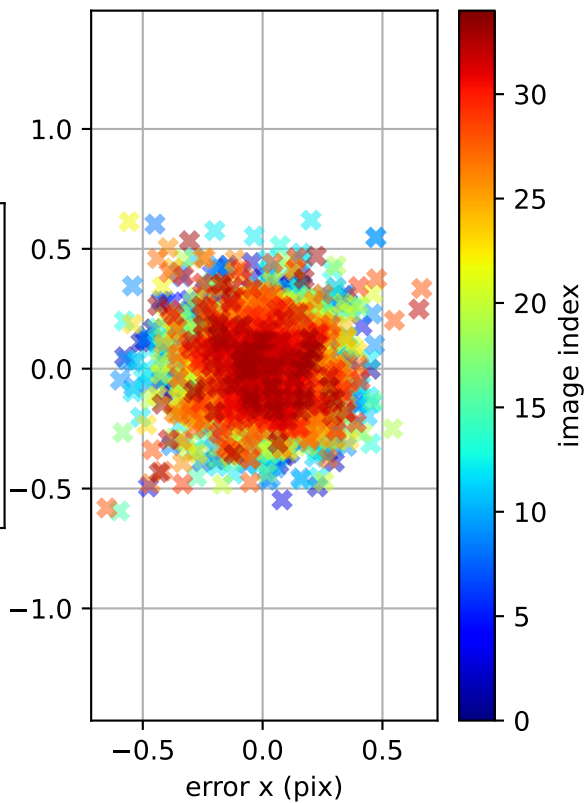
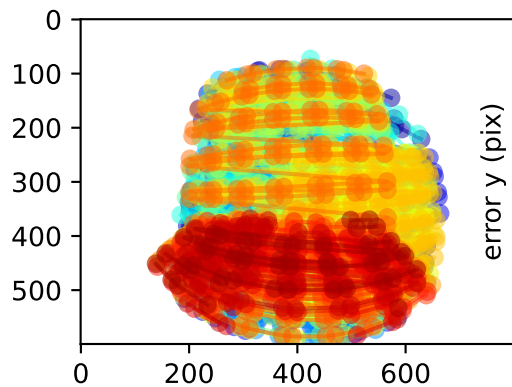
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

