

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18475709 0.0215289 -0.0043314 0.00033676] +- [0.00308077 0.00757517 0.00712735 0.0022482]

projection: [603.64550465 603.67616168 1005.99322165 536.15639092] +- [0.48769573 0.47655801 0.20448795
0.19039603]

reprojection error: [0.000018, 0.000000] +- [0.550648, 0.583704]

Target configuration

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Type: aprilgrid

Tags:

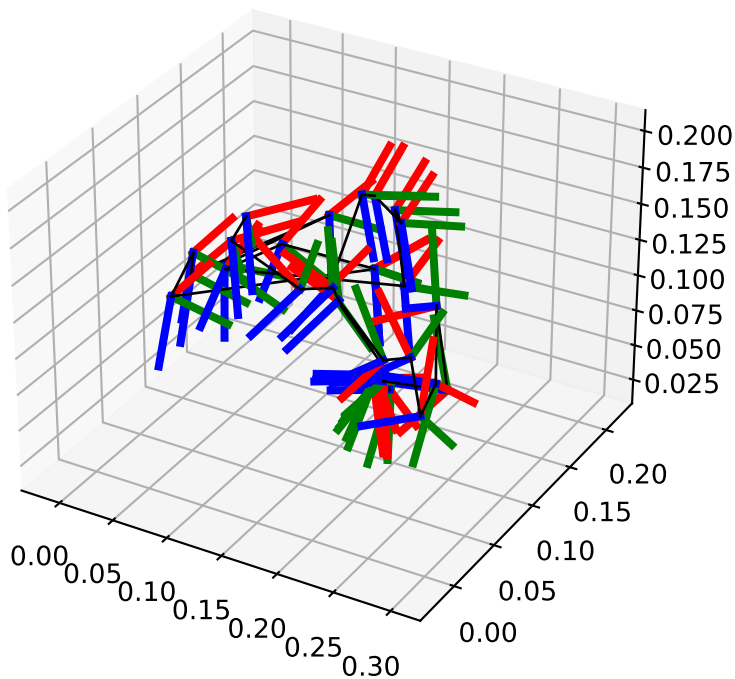
Rows: 6

Cols: 6

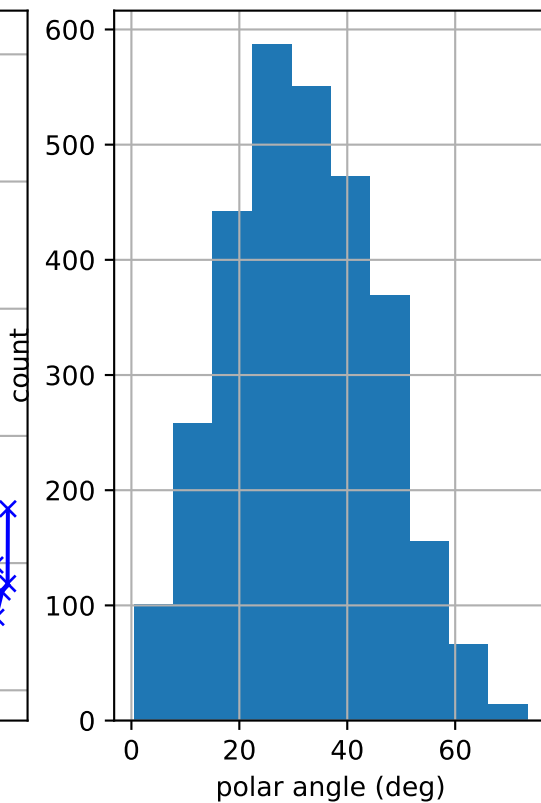
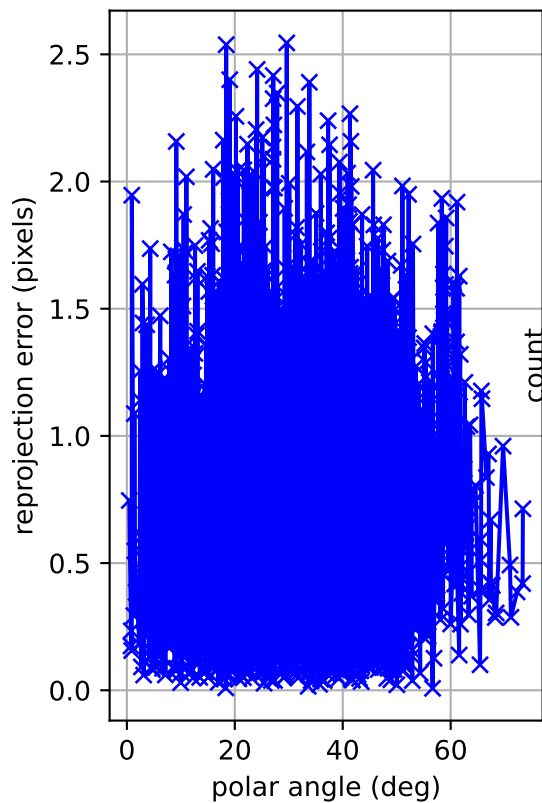
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

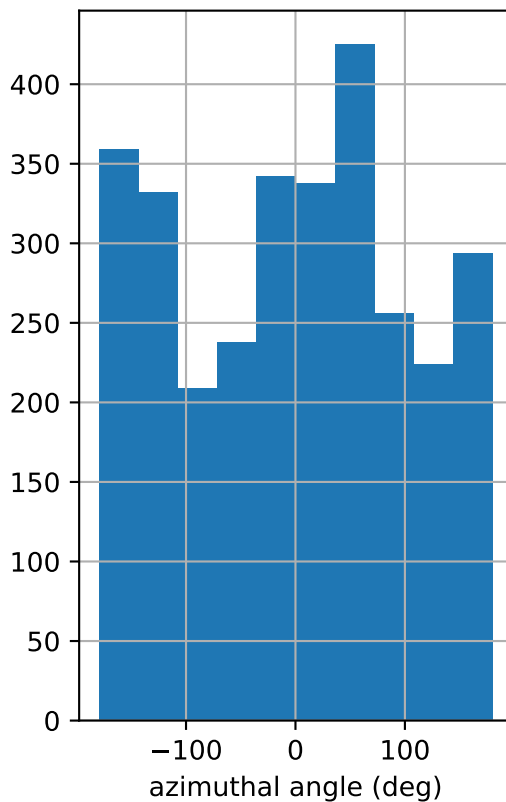
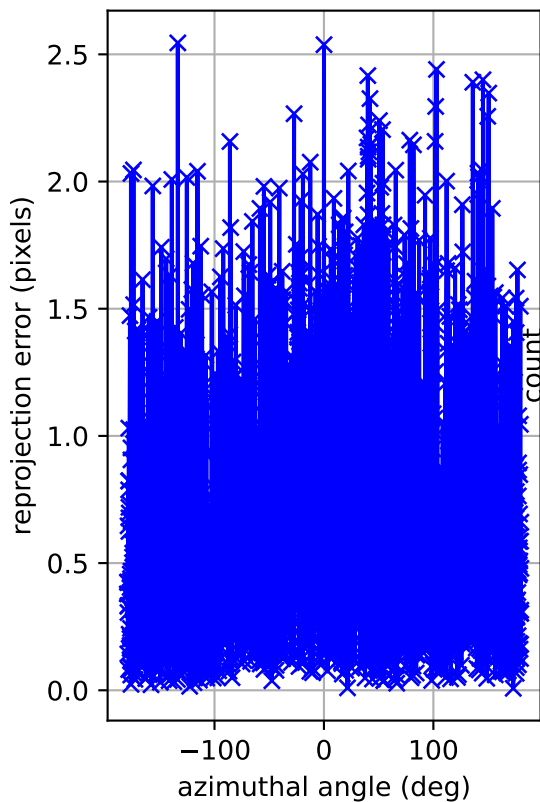
cam0: estimated poses



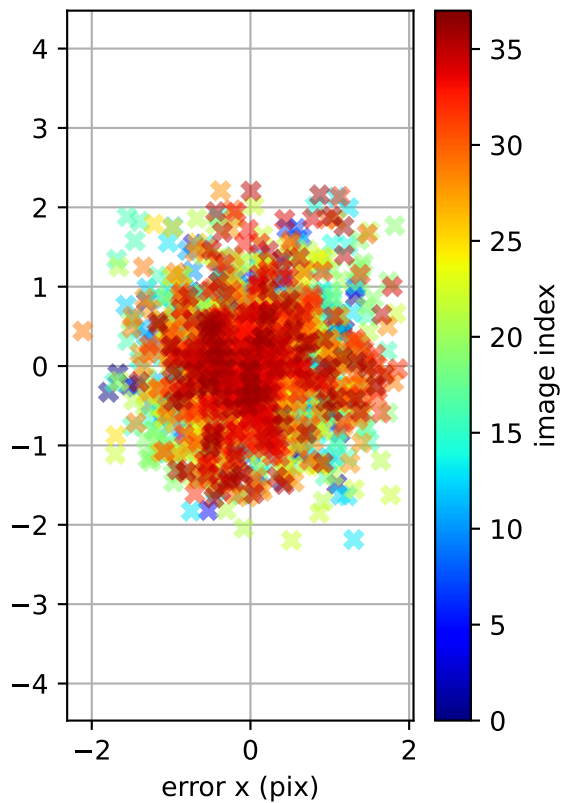
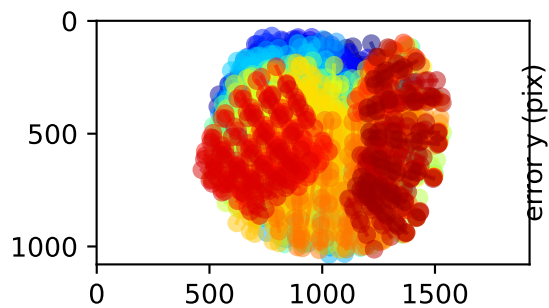
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

