

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.17905253 0.00395981 0.00920284 -0.00283072] +- [0.00605212 0.0153304 0.01474427 0.00468653]

projection: [269.53582977 269.64507936 340.78010526 238.38769719] +- [0.4786446 0.45805494 0.20478328
0.17355328]

reprojection error: [0.000001, -0.000001] +- [0.156979, 0.155080]

Target configuration

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Type: aprilgrid

Tags:

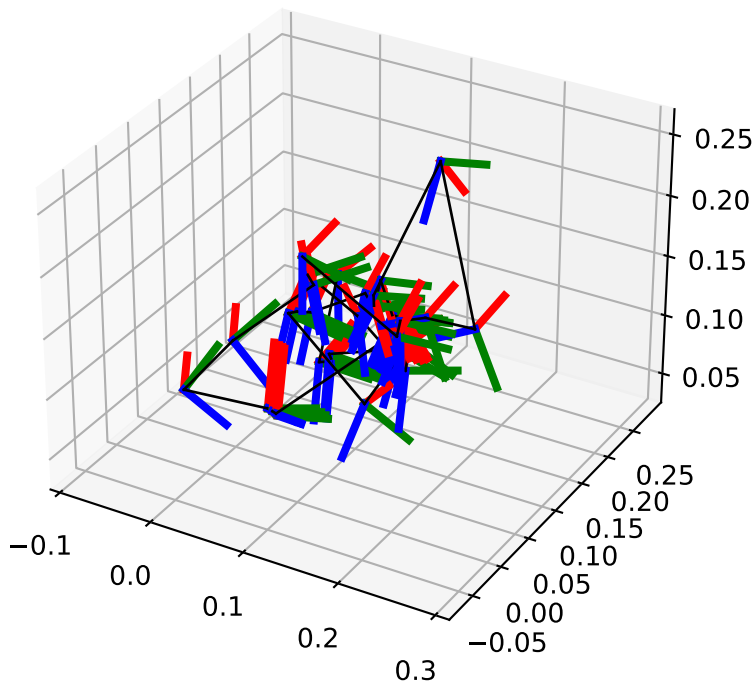
Rows: 6

Cols: 6

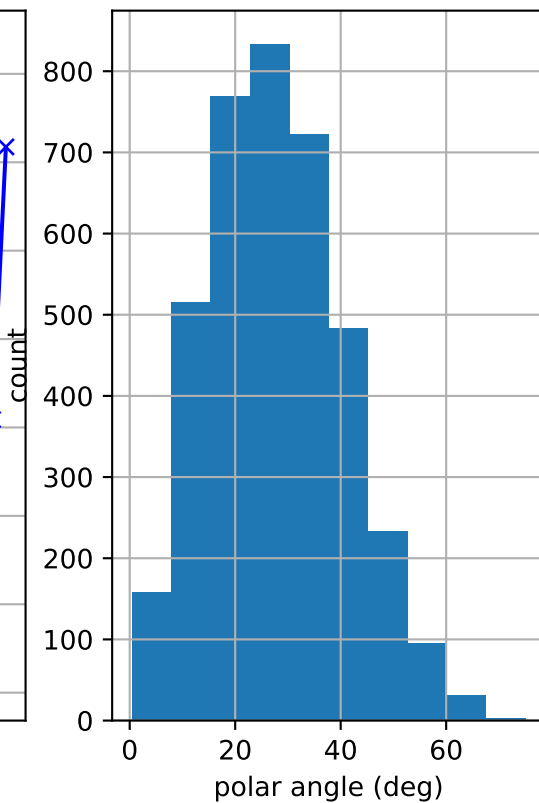
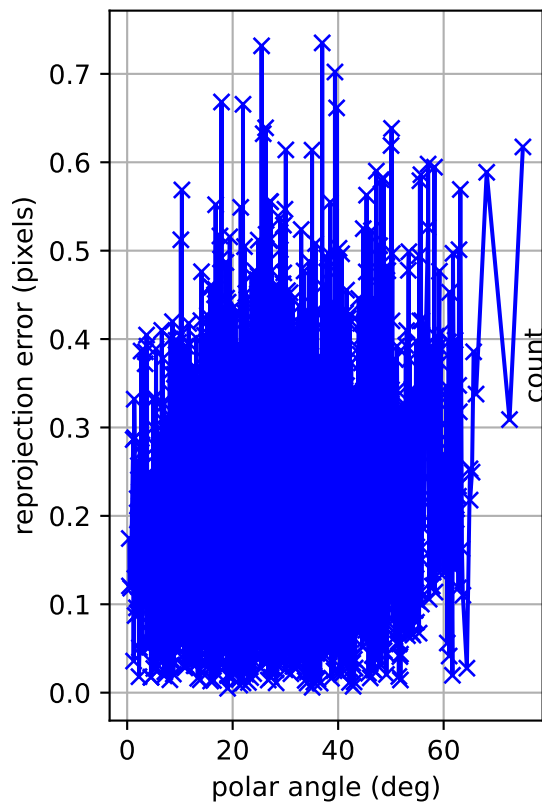
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

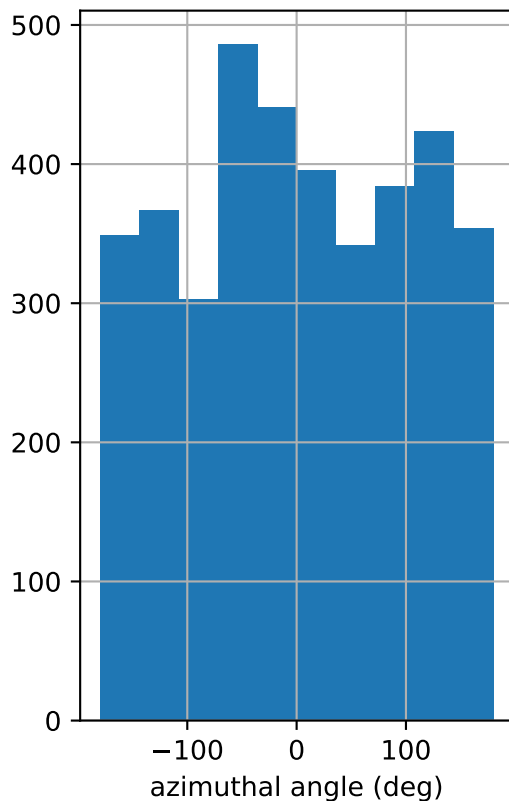
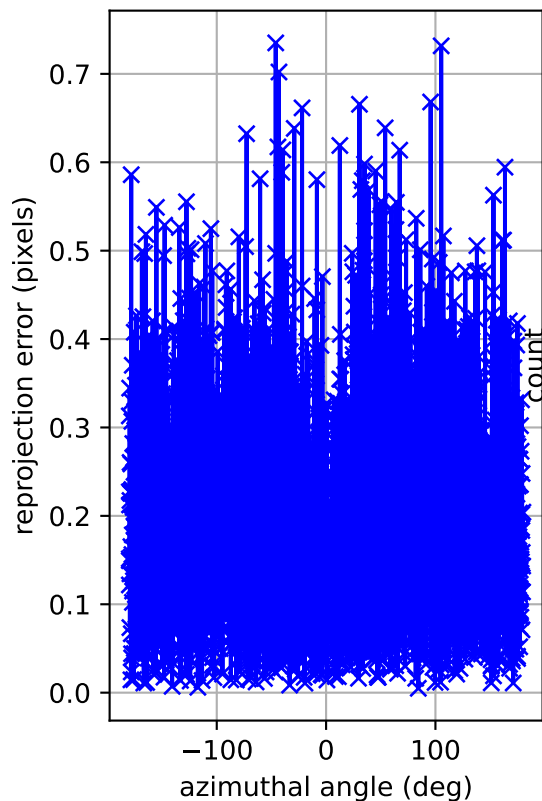
cam0: estimated poses



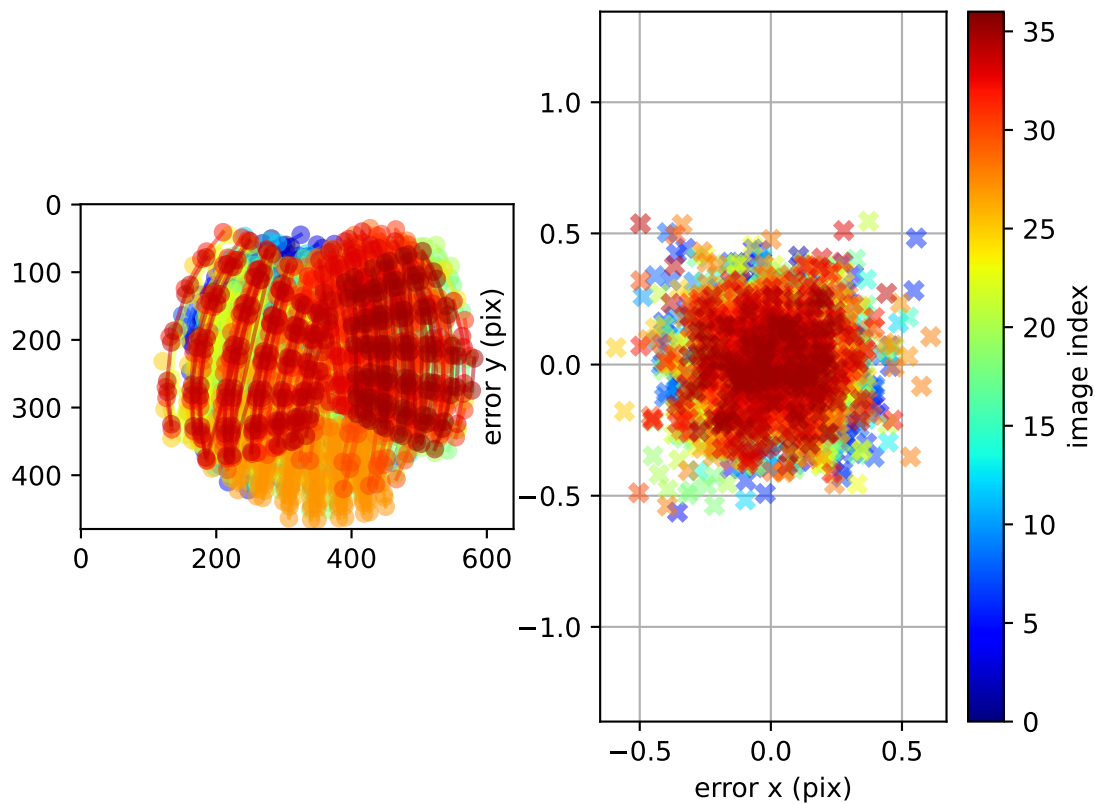
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

