Calibration results
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Camera-system parameters:
cam0 (/usb_cam/image_raw):
    type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
    distortion: [-0.18983128 0.01725228 -0.00727174 0.00533771] +- [0.01047039 0.0405078 0.06124335 0.03106133]
    projection: [338.41492182 338.72192311 421.56434724 300.74873529] +- [0.81733916 0.90019181 0.263129
0.28123526]
    reprojection error: [-0.000002, 0.000002] +- [0.171061, 0.161416]

Target configuration
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  Type: aprilgrid
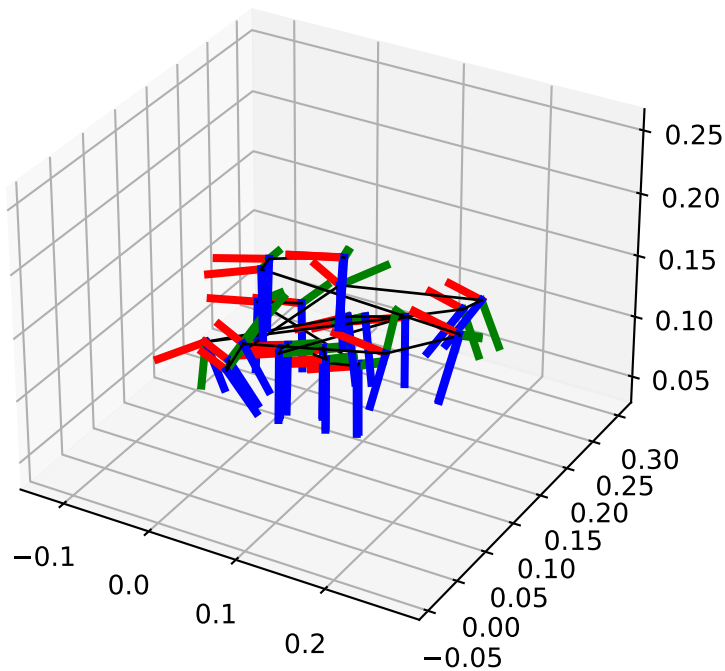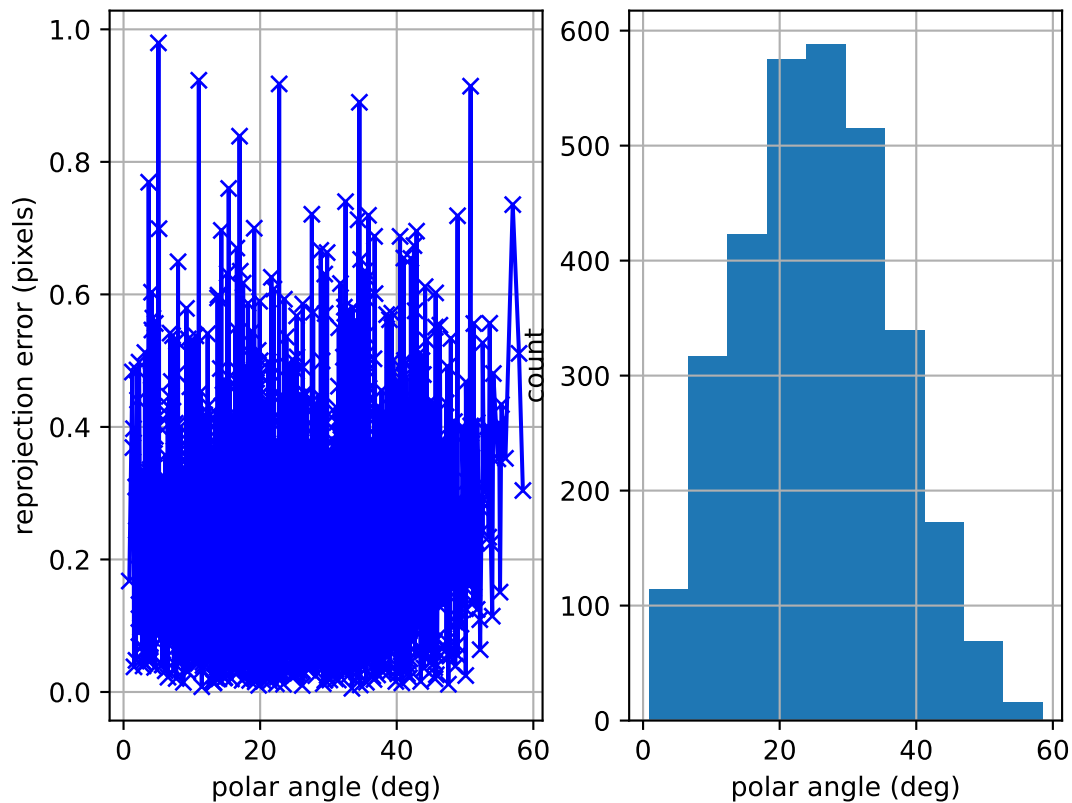 Tags:
    Rows: 6
    Cols: 6
    Size: 0.022 [m]
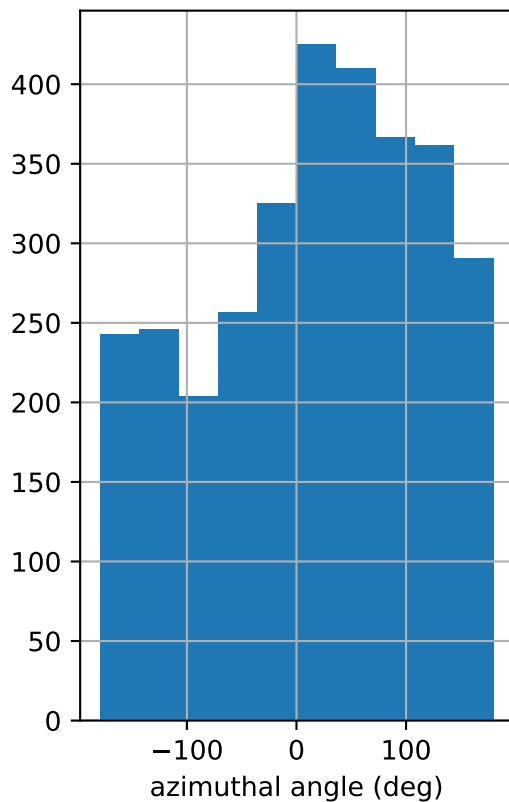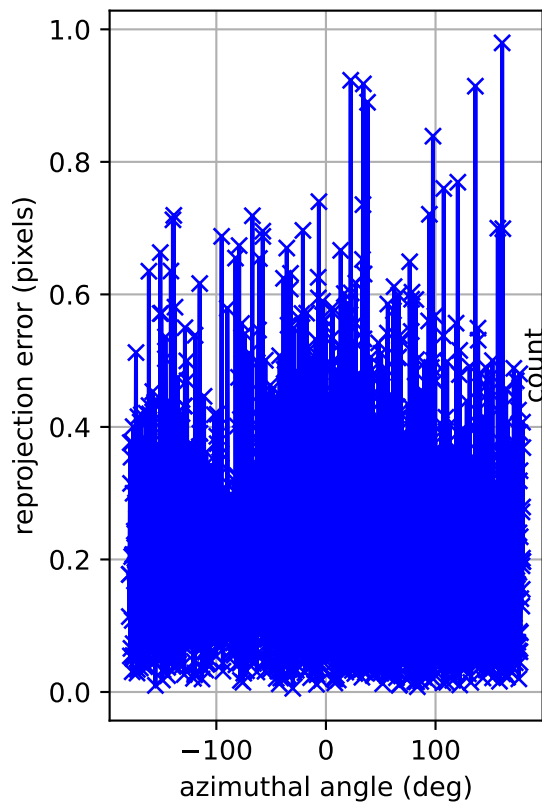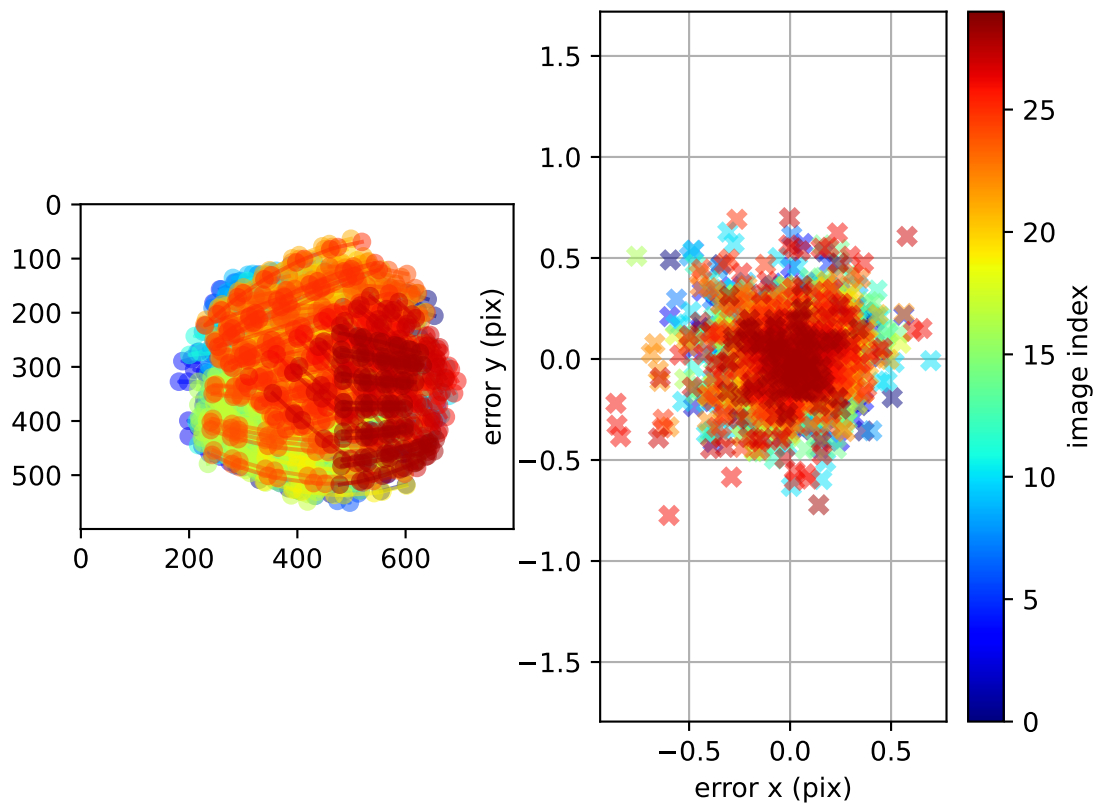   Spacing 0.006599999999999999 [m]

cam0: estimated poses

cam0: polar error

cam0: azimuthal error

cam0: reprojection errors

Location of removed outlier corners

cam0