

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18799013 0.03490149 -0.02088604 0.00685953] +- [0.00492796 0.01577534 0.01992711 0.00851814]

projection: [597.2053985 597.70163797 1002.73782409 558.21925284] +- [0.82759903 0.87920047 0.22101351
0.24237871]

reprojection error: [-0.000037, 0.000001] +- [0.876252, 0.830697]

Target configuration

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Type: aprilgrid

Tags:

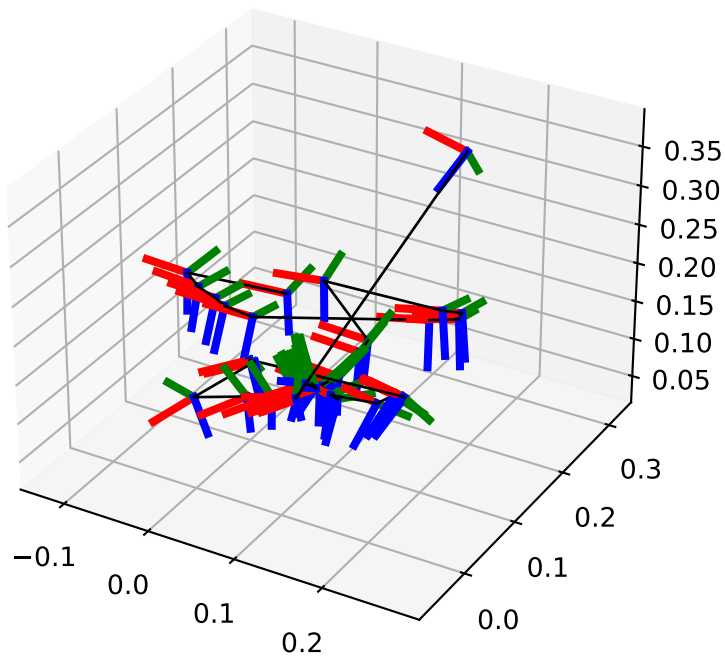
Rows: 6

Cols: 6

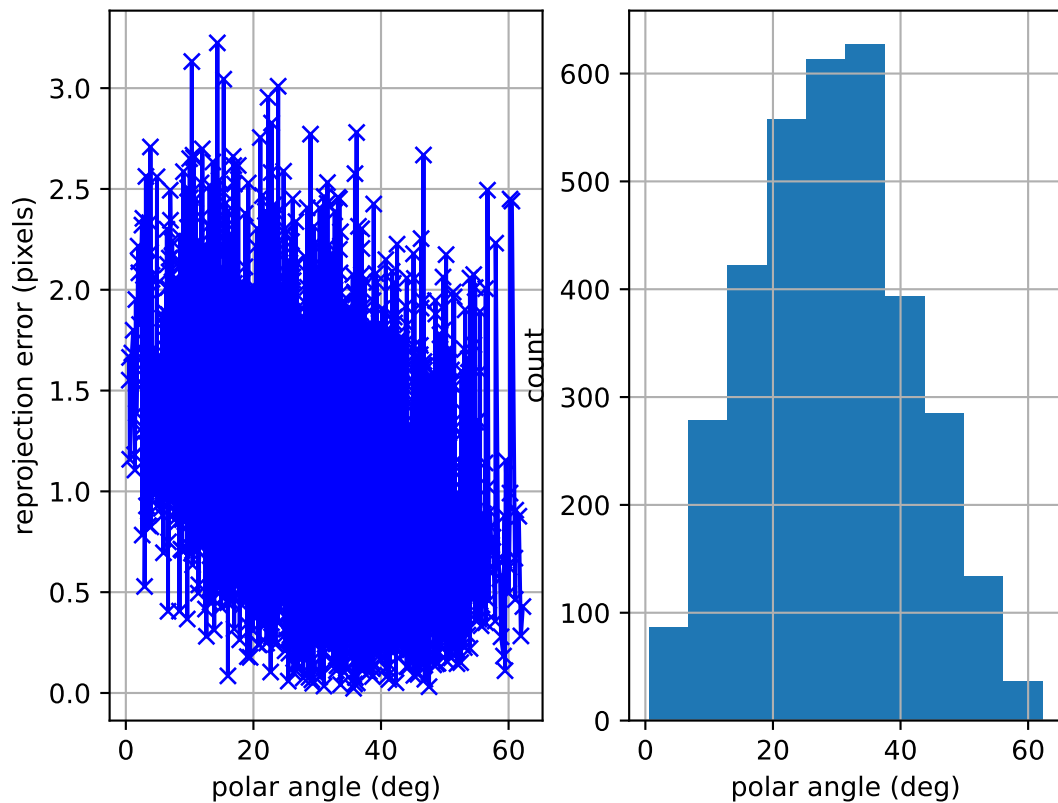
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

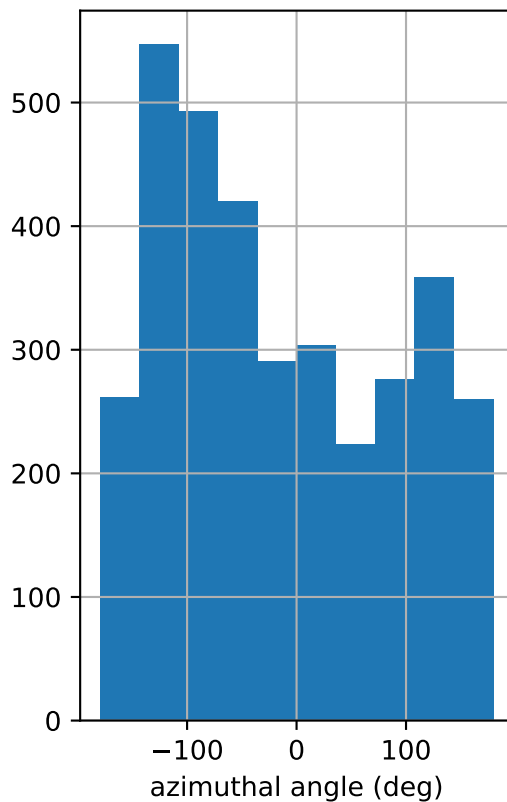
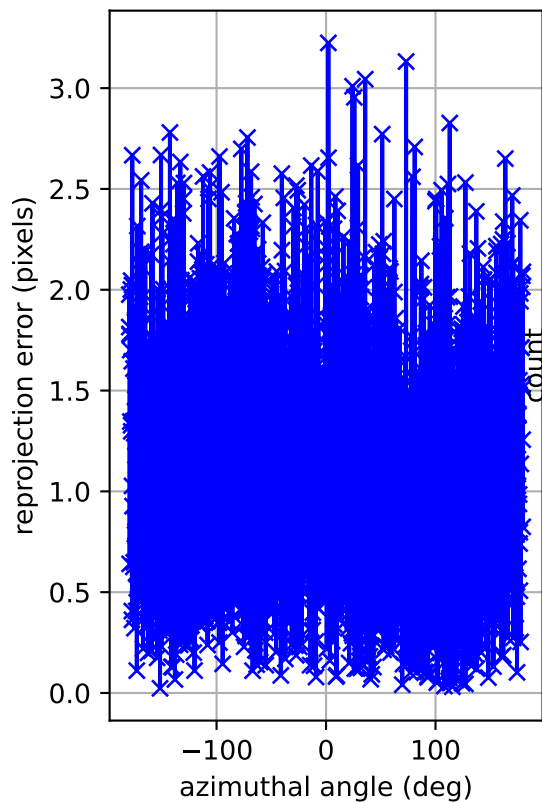
cam0: estimated poses



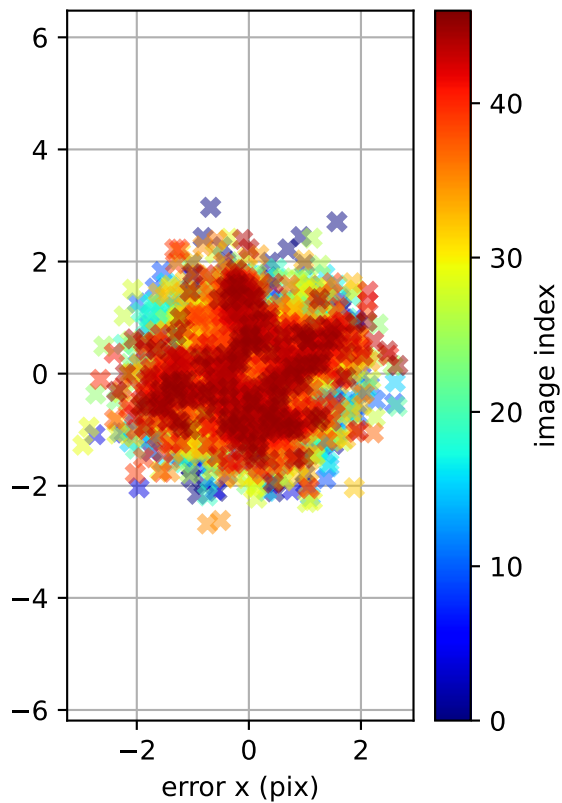
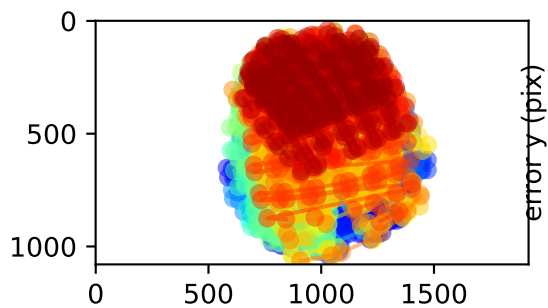
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

