

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18902427 0.02581124 -0.00663928 0.00061407] +- [0.00344278 0.0098996 0.01105423 0.00414606]

projection: [569.19310253 569.38331698 681.06140549 527.09476015] +- [0.53876732 0.59486313 0.16675189
0.20040579]

reprojection error: [0.000018, -0.000015] +- [0.731225, 0.745184]

Target configuration

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Type: aprilgrid

Tags:

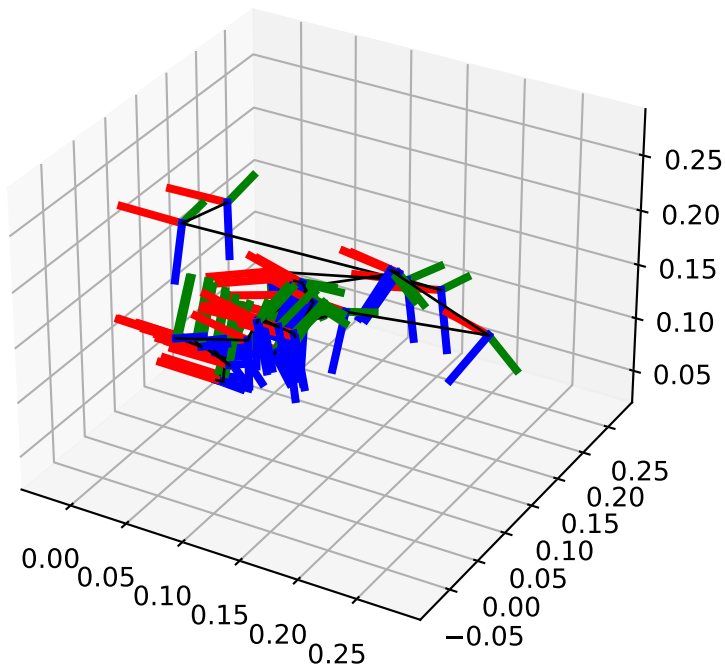
Rows: 6

Cols: 6

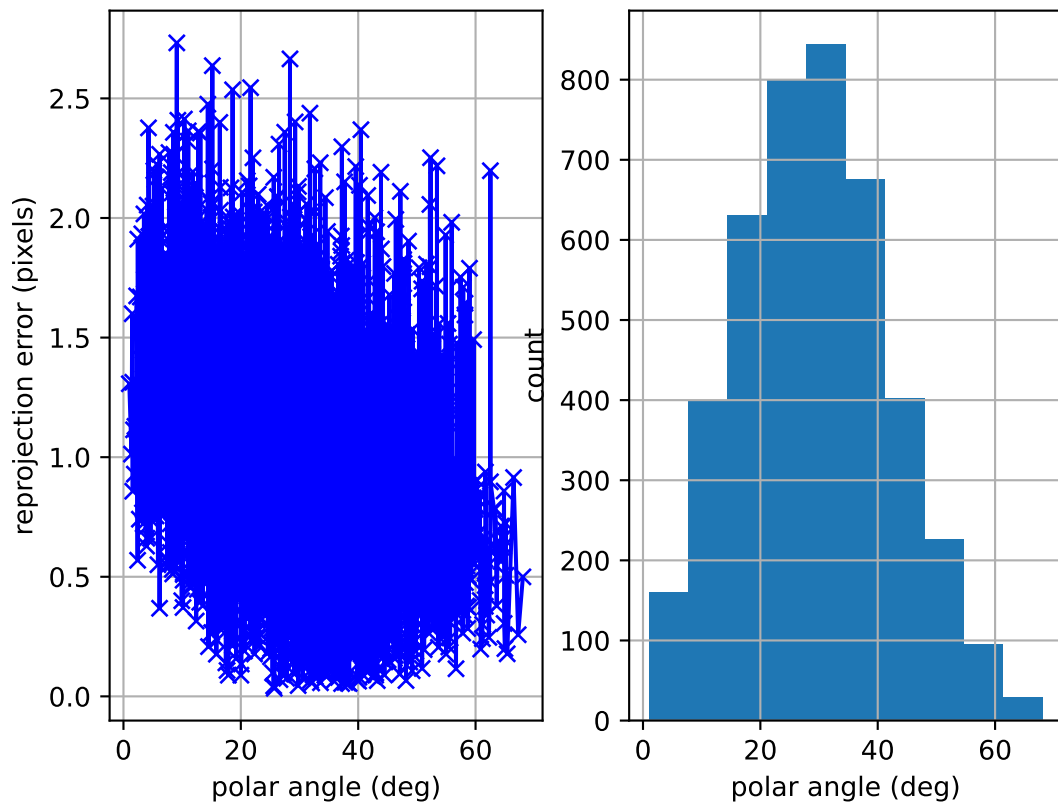
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

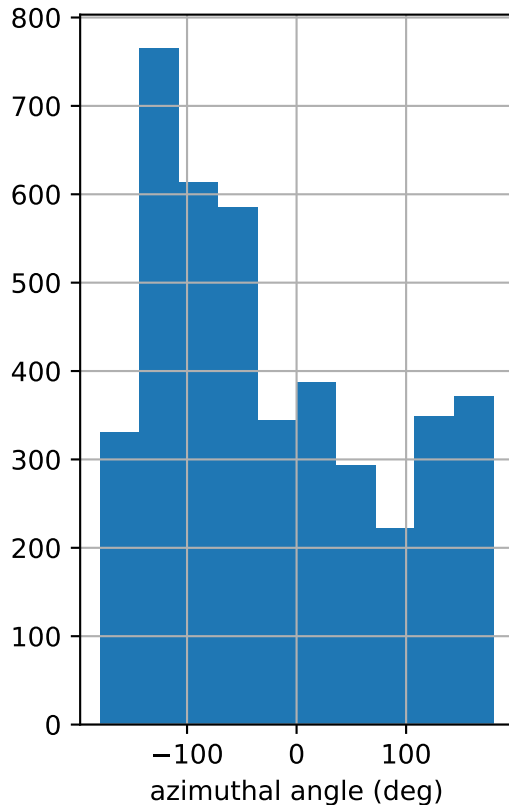
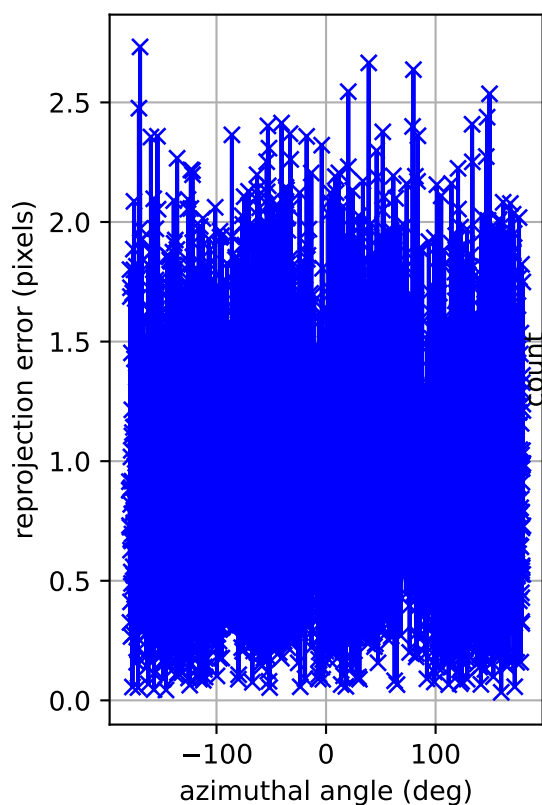
cam0: estimated poses



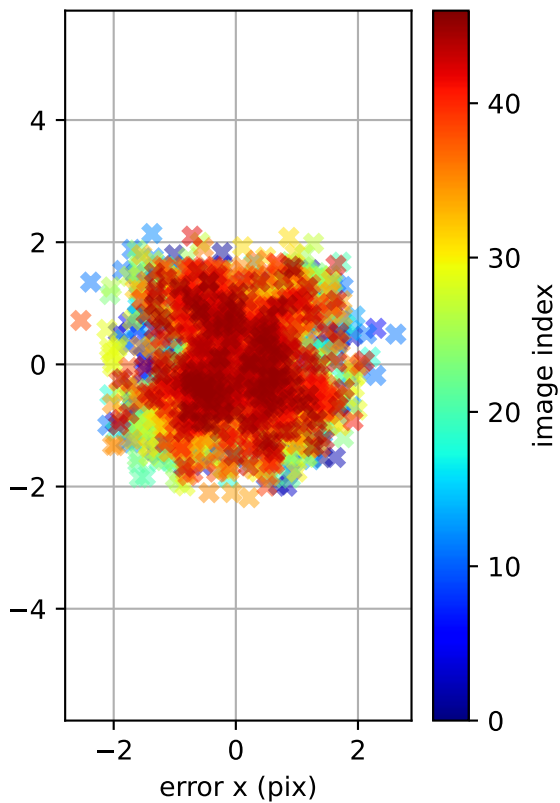
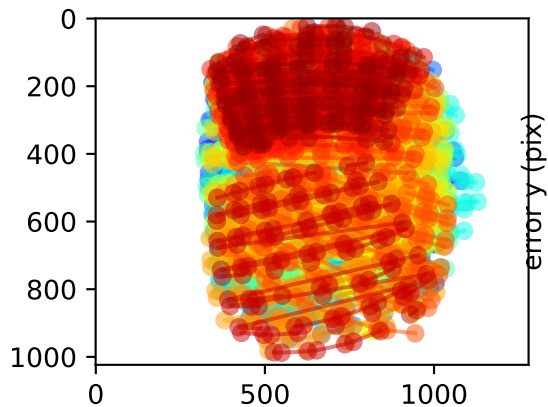
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

