Calibration results
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Camera-system parameters:
cam0 (/usb_cam/image_raw):
    type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
    distortion: [-0.18106984 -0.00051017 0.01968023 -0.0078272] +- [0.00566584 0.0189908 0.02508038 0.01125538]
    projection: [429.50767435 429.66885584 546.93887249 399.72972388] +- [0.65030125 0.68805927 0.2038953
0.20901092]
    reprojection error: [0.000002, 0.000002] +- [0.542202, 0.511924]

Target configuration
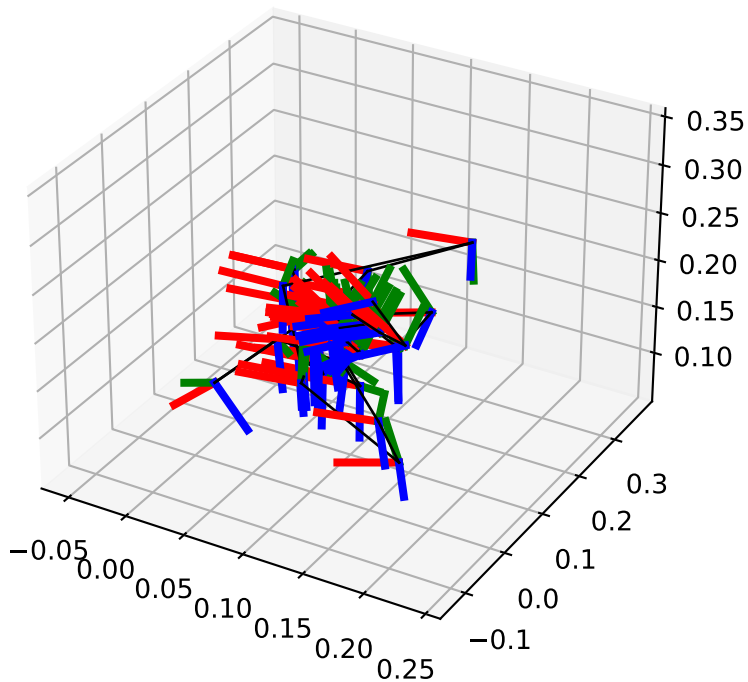====================
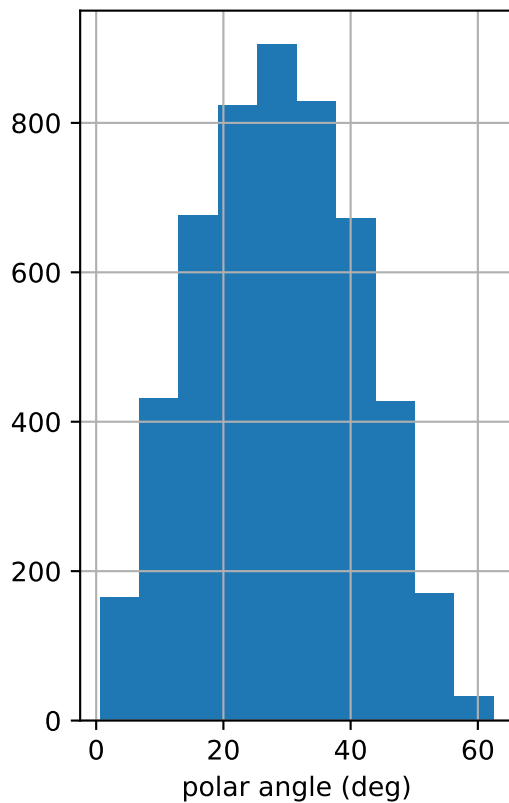
  Type: aprilgrid
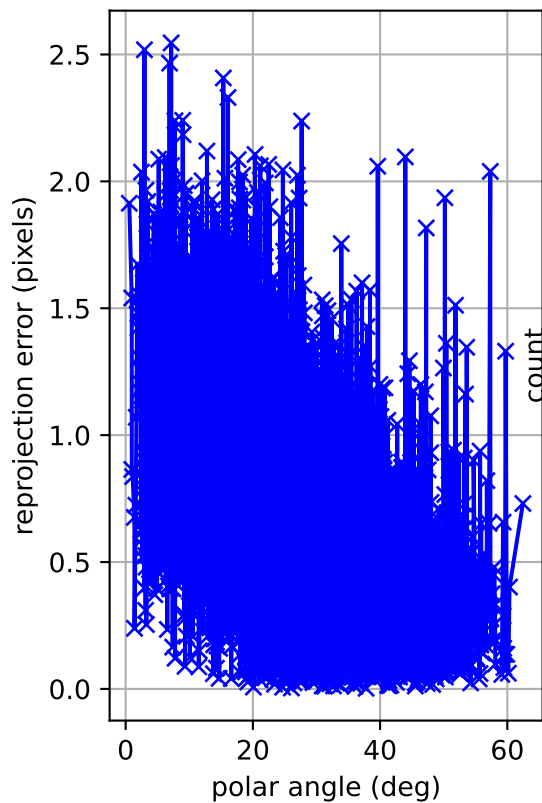 Tags:
    Rows: 6
    Cols: 6
    Size: 0.022 [m]
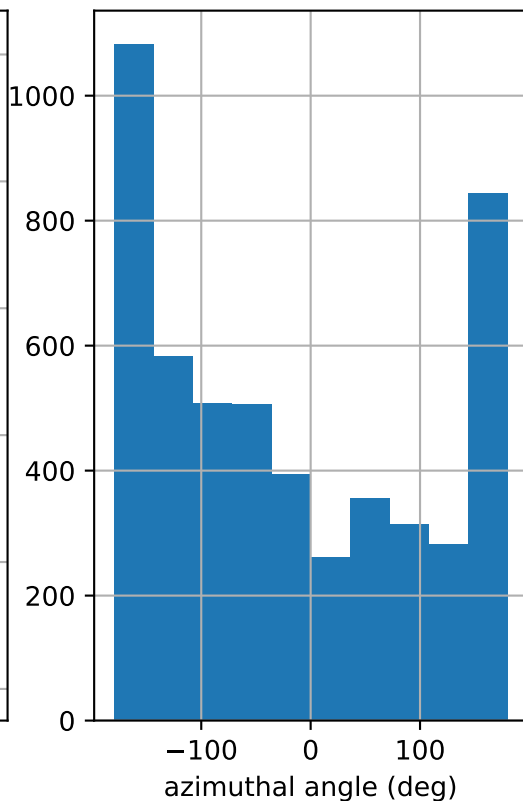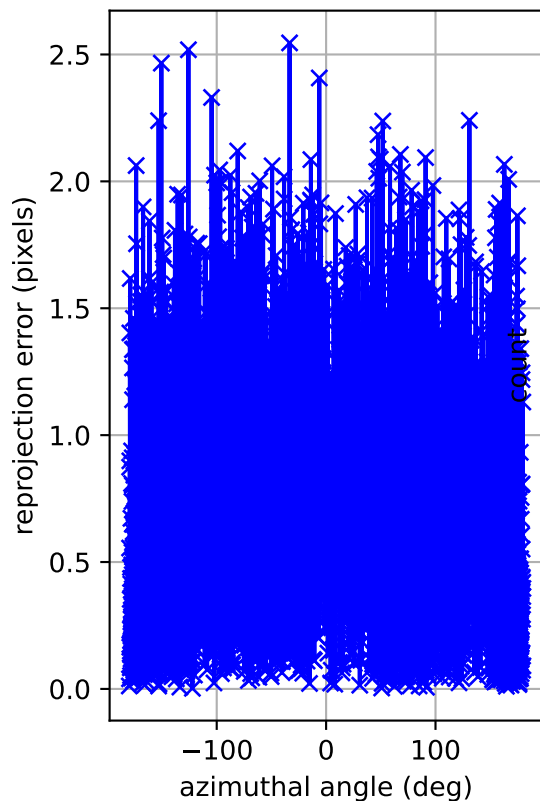   Spacing 0.006599999999999999 [m]
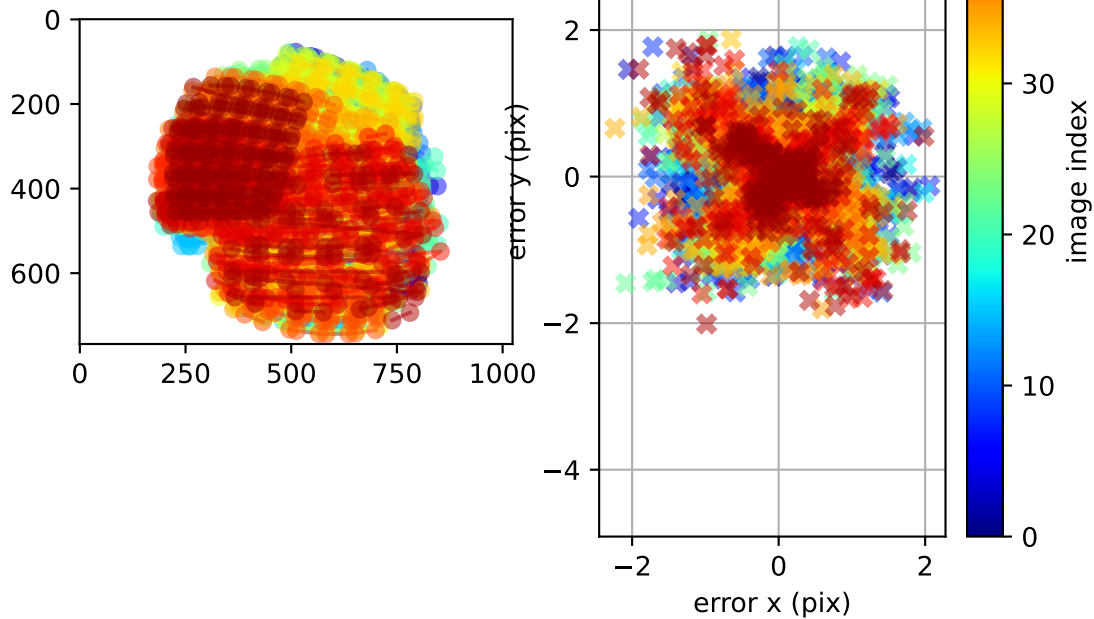
cam0: estimated poses

cam0: polar error

cam0: azimuthal error

cam0: reprojection errors

Location of removed outlier corners

cam0