

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18313444 0.00860263 0.00801362 -0.00293123] +- [0.00875374 0.0272013 0.03295515 0.013457]

projection: [268.05640776 268.09170697 315.60653086 239.39359036] +- [0.53215064 0.57113178 0.22214766
0.22294584]

reprojection error: [0.000001, -0.000001] +- [0.134754, 0.134345]

Target configuration

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Type: aprilgrid

Tags:

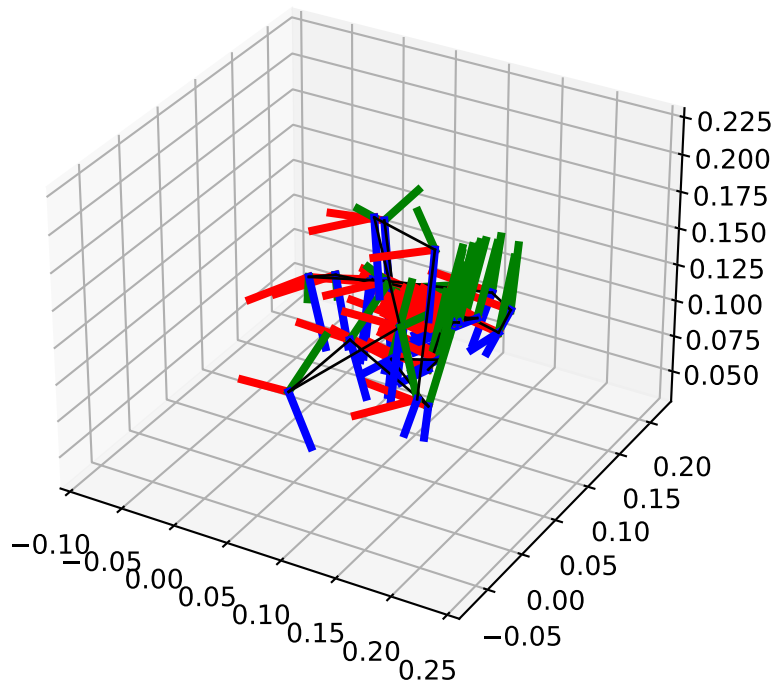
Rows: 6

Cols: 6

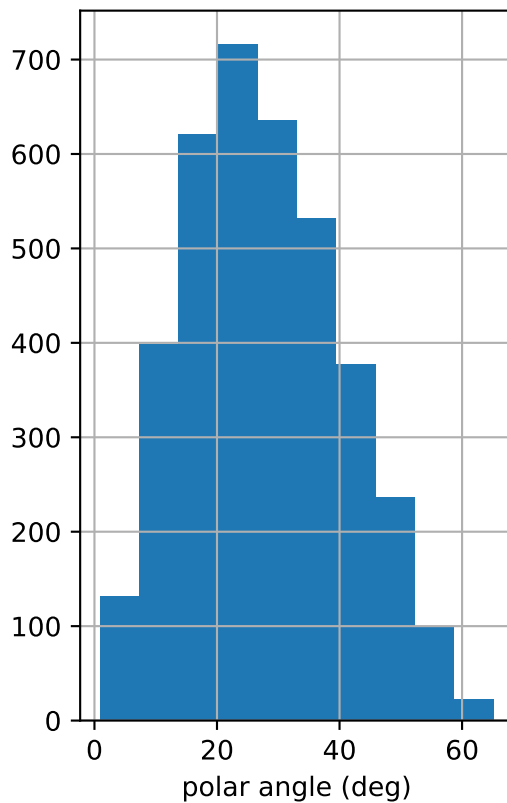
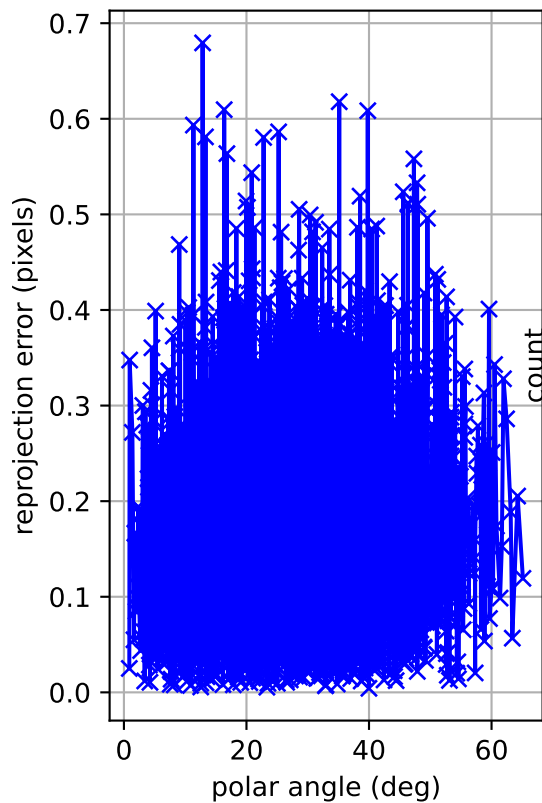
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

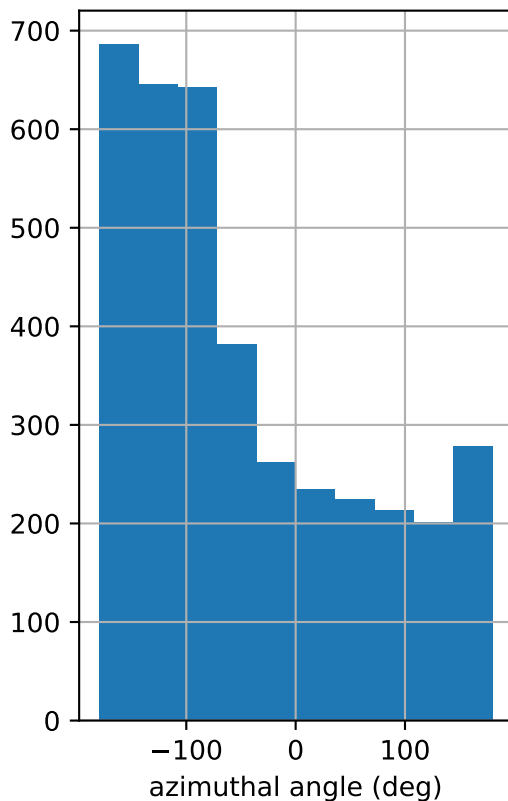
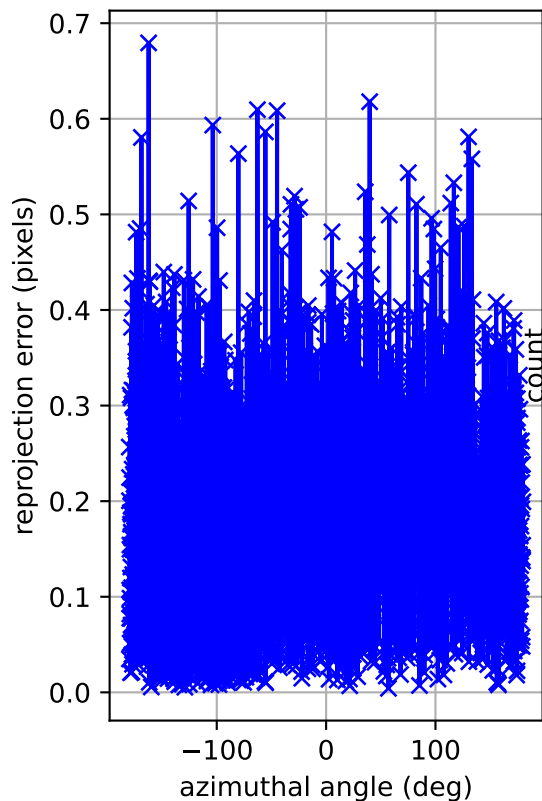
cam0: estimated poses



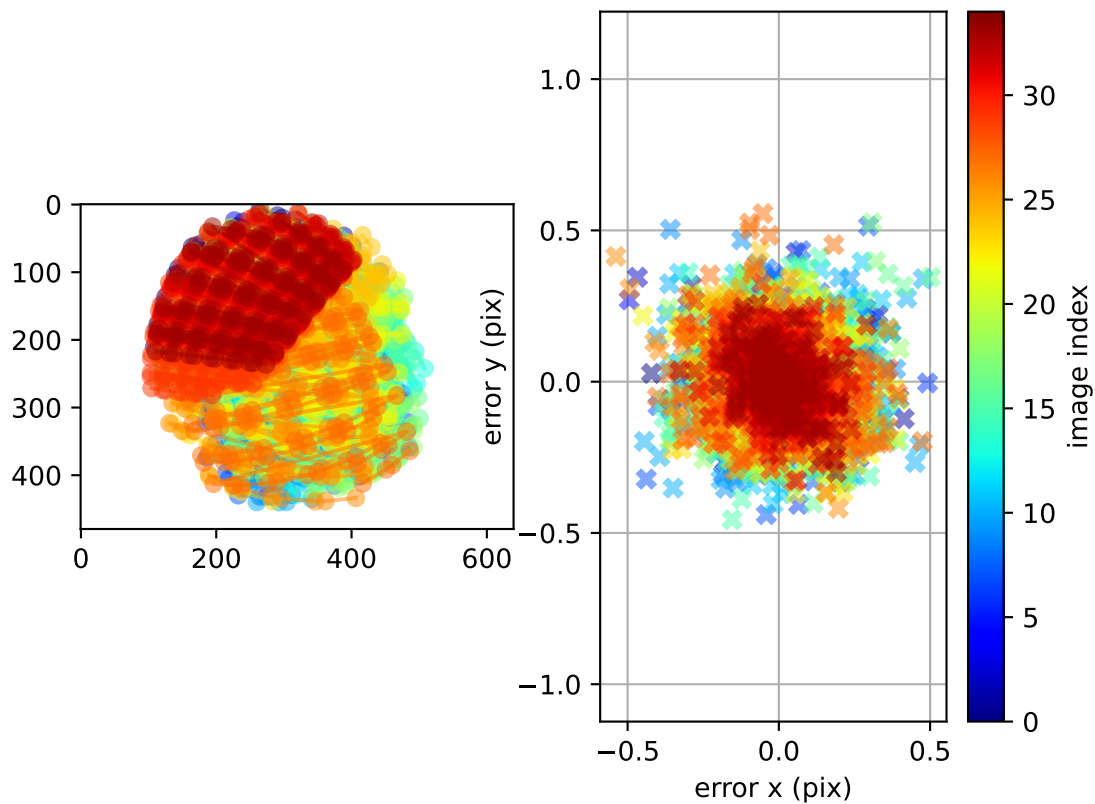
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



cam0

