Calibration results
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Camera-system parameters:
cam0 (/usb_cam/image_raw):
    type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
    distortion: [-0.18696386 0.02084052 -0.00536361 0.00141557] +- [0.00292842 0.00690045 0.00622081 0.0018816]
    projection: [575.34883907 575.42139709 683.73781121 508.05244152] +- [0.4209216 0.48020817 0.18049218
0.21424022]
    reprojection error: [-0.000021, -0.000024] +- [0.307326, 0.338067]

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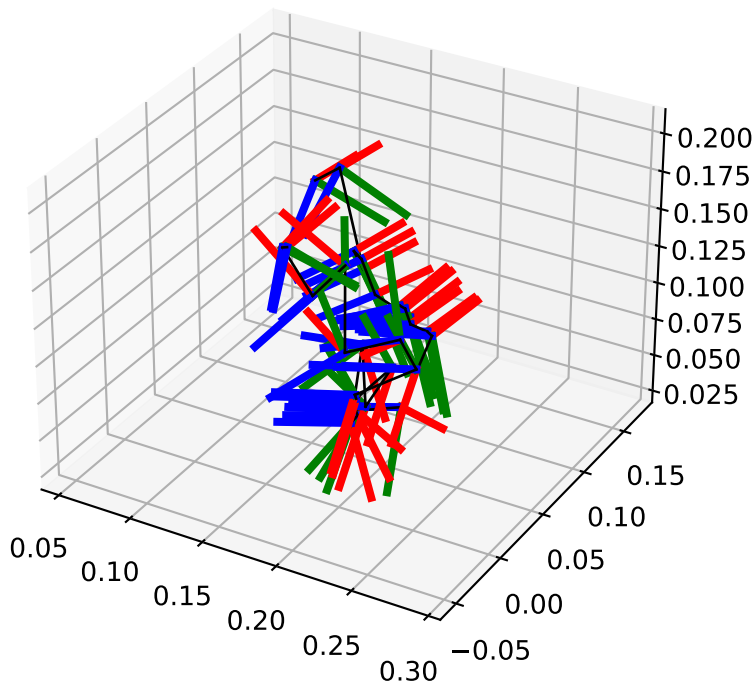====================
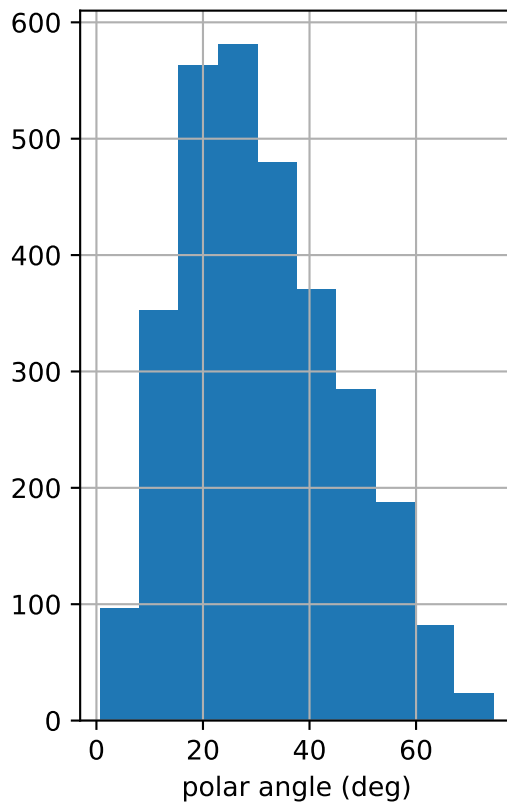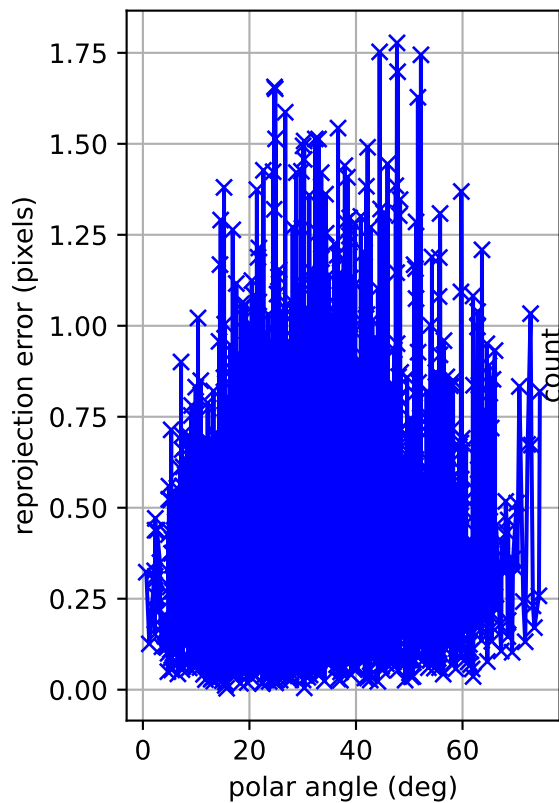
  Type: aprilgrid
  Tags:
    Rows: 6
    Cols: 6
    Size: 0.022 [m]
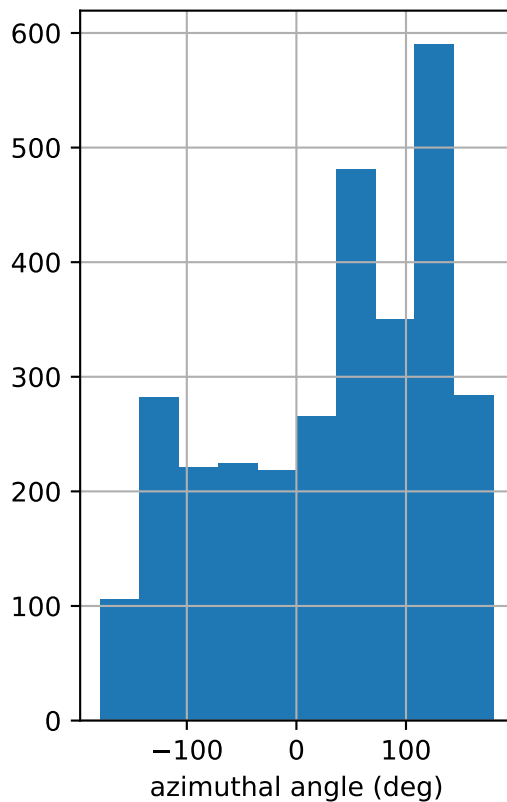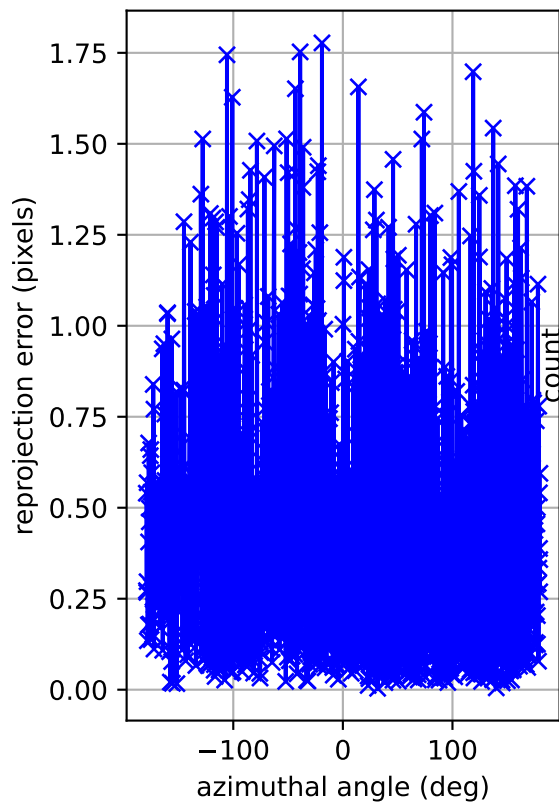   Spacing 0.006599999999999999 [m]
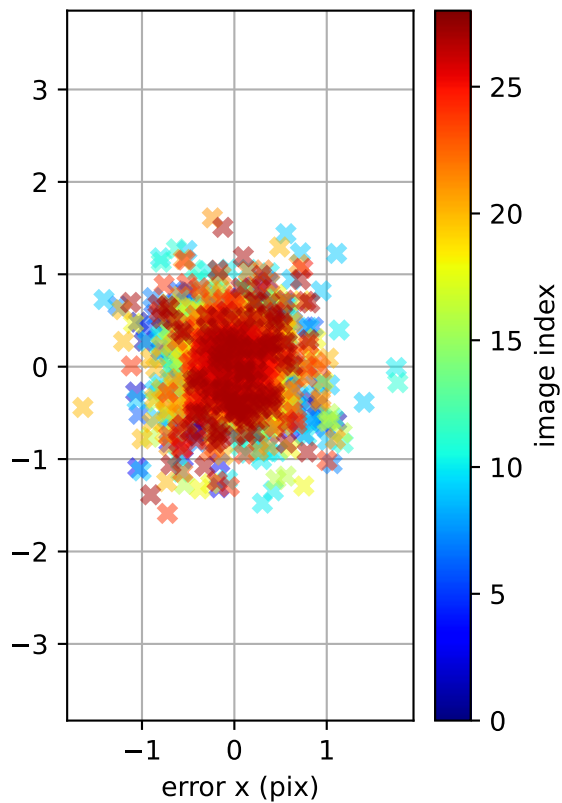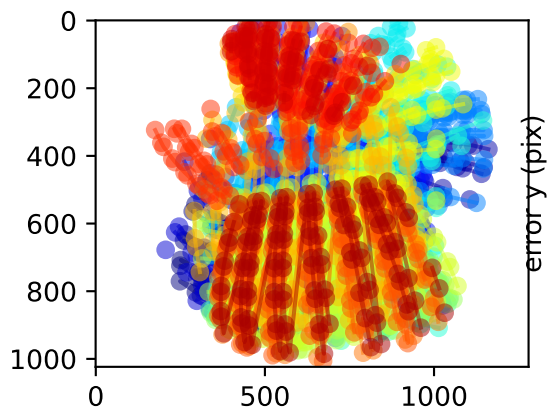
cam0: estimated poses

cam0: polar error

cam0: azimuthal error

cam0: reprojection errors

Location of removed outlier corners

cam0