

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.19055029 0.02883511 -0.01148809 0.00301319] +- [0.00775362 0.02476522 0.03038454 0.01256396]

projection: [268.66871893 268.86965713 334.49535143 243.0071038] +- [0.42503285 0.45162071 0.18115103
0.18276452]

reprojection error: [-0.000001, -0.000000] +- [0.138534, 0.135881]

Target configuration

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Type: aprilgrid

Tags:

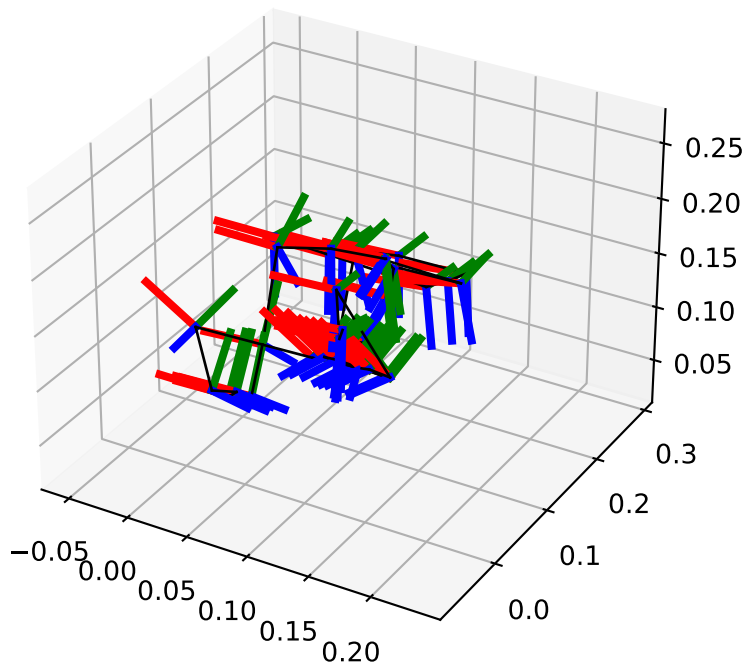
Rows: 6

Cols: 6

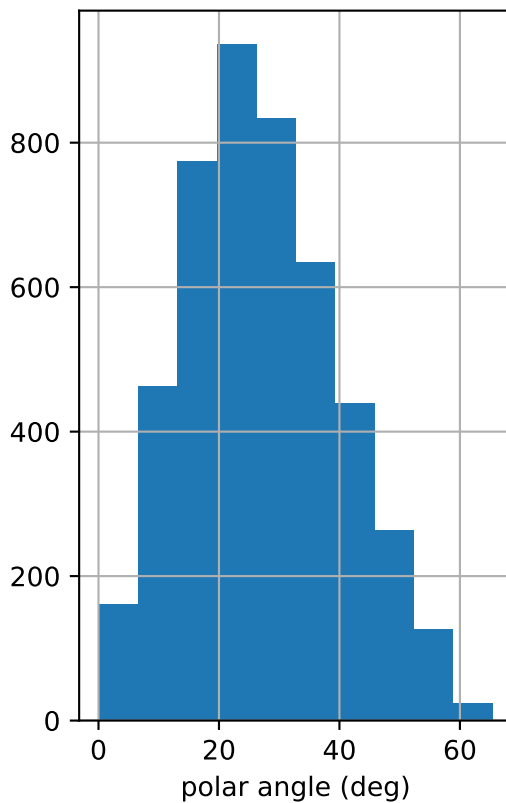
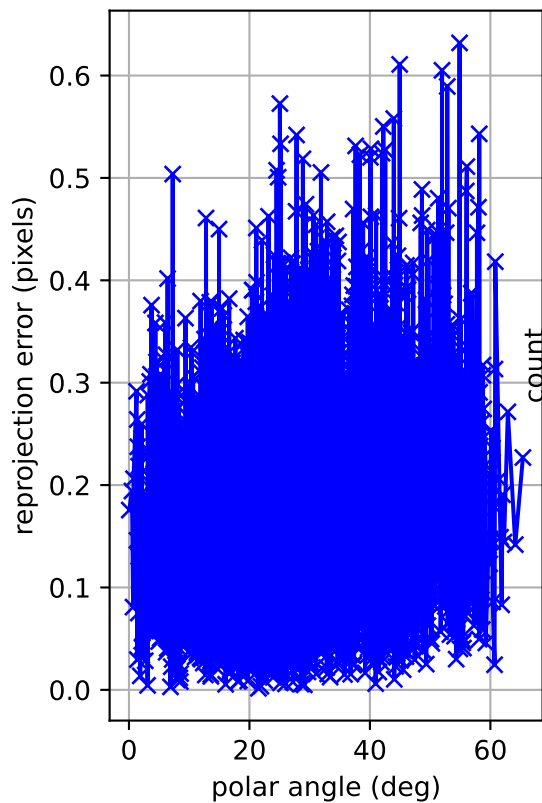
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

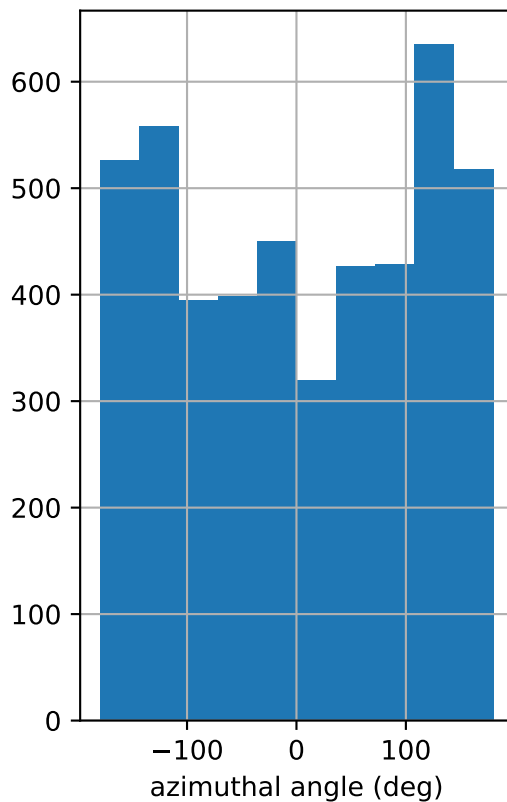
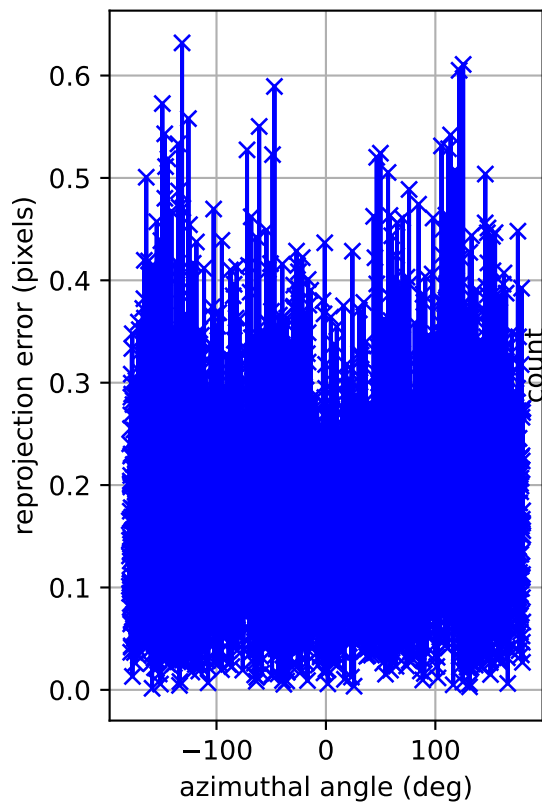
cam0: estimated poses



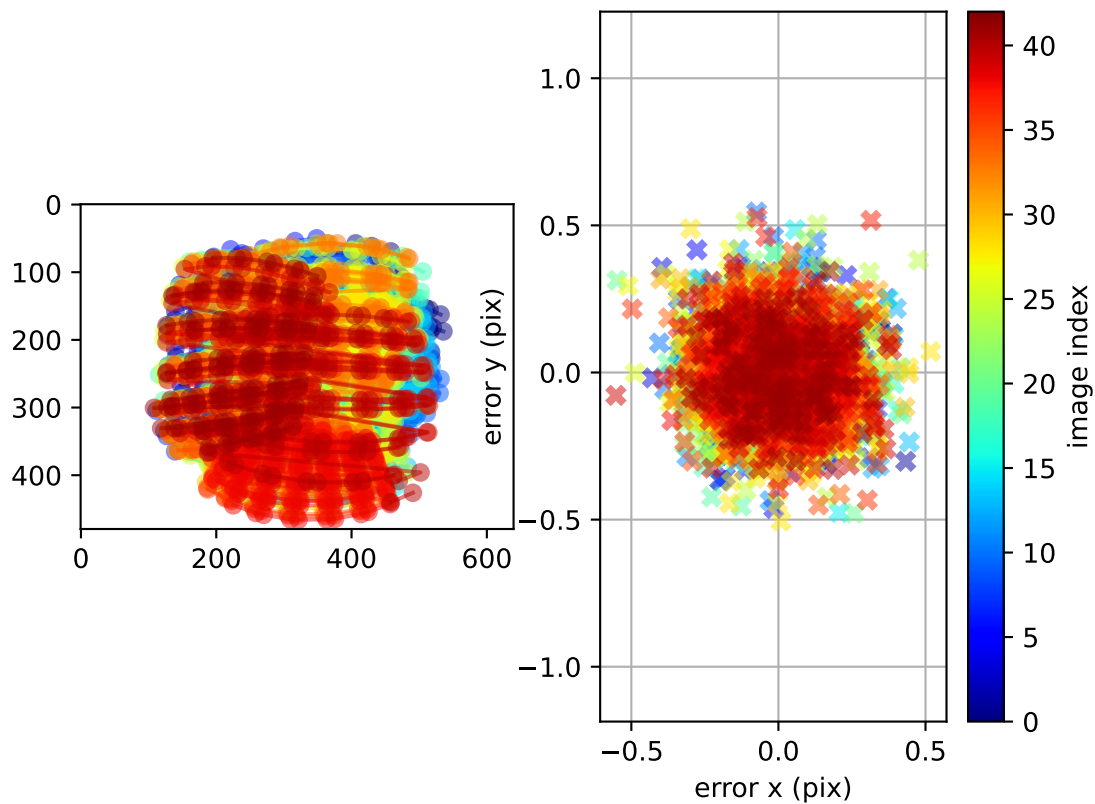
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

