

Calibration results

=====

Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18263595 0.00754393 0.00727525 -0.00226599] +- [0.00425962 0.00980827 0.00874177 0.00262692]

projection: [434.3609095 434.46420573 547.08516705 384.70811355] +- [0.49388408 0.50164403 0.23920104
0.17323931]

reprojection error: [0.000001, 0.000001] +- [0.205696, 0.261706]

Target configuration

=====

Type: aprilgrid

Tags:

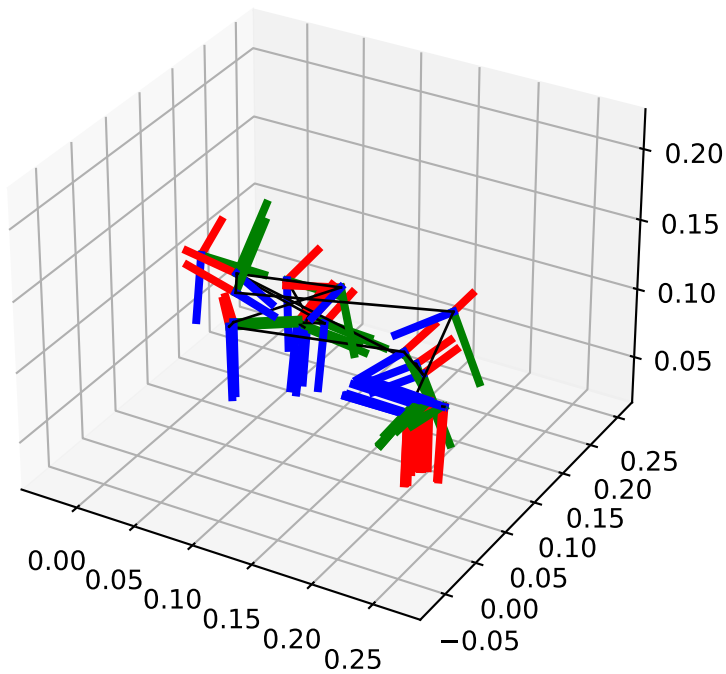
Rows: 6

Cols: 6

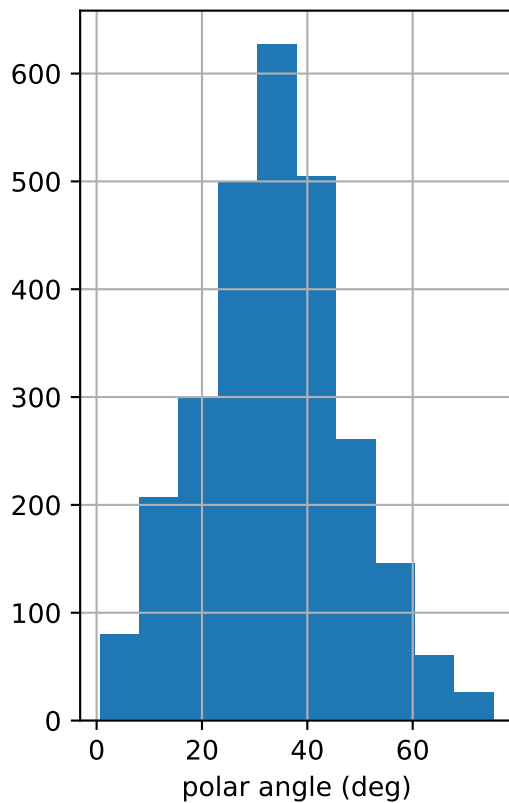
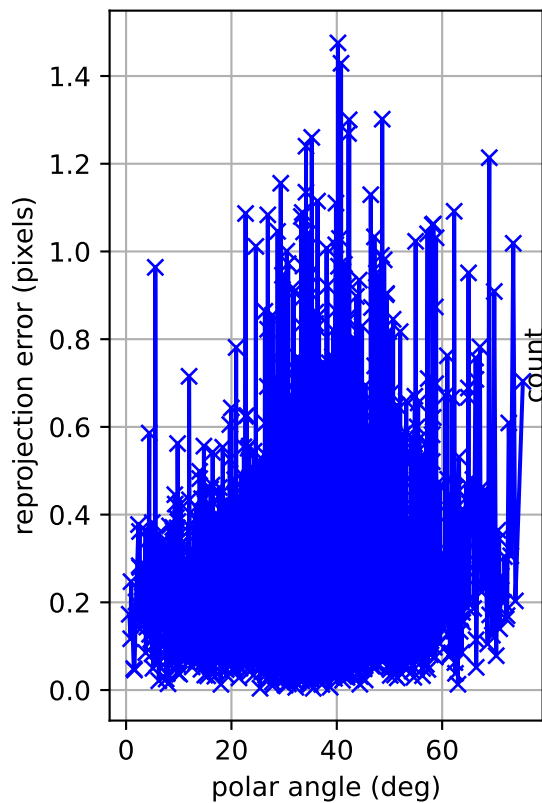
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

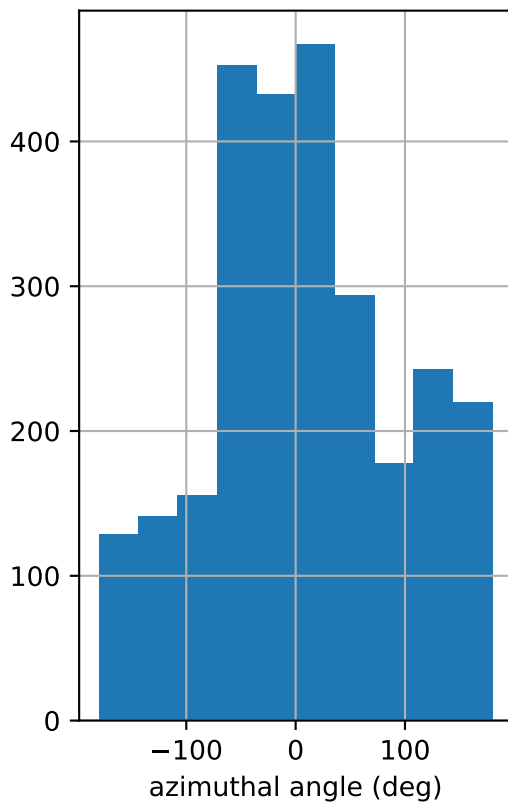
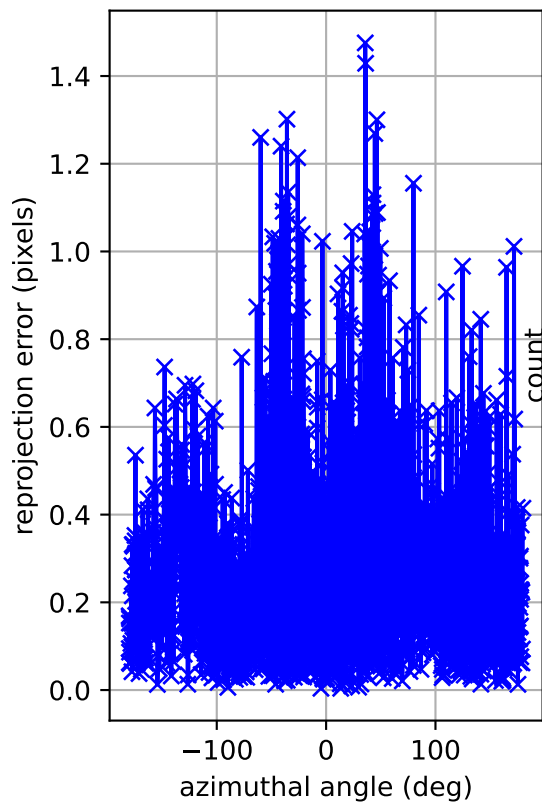
cam0: estimated poses



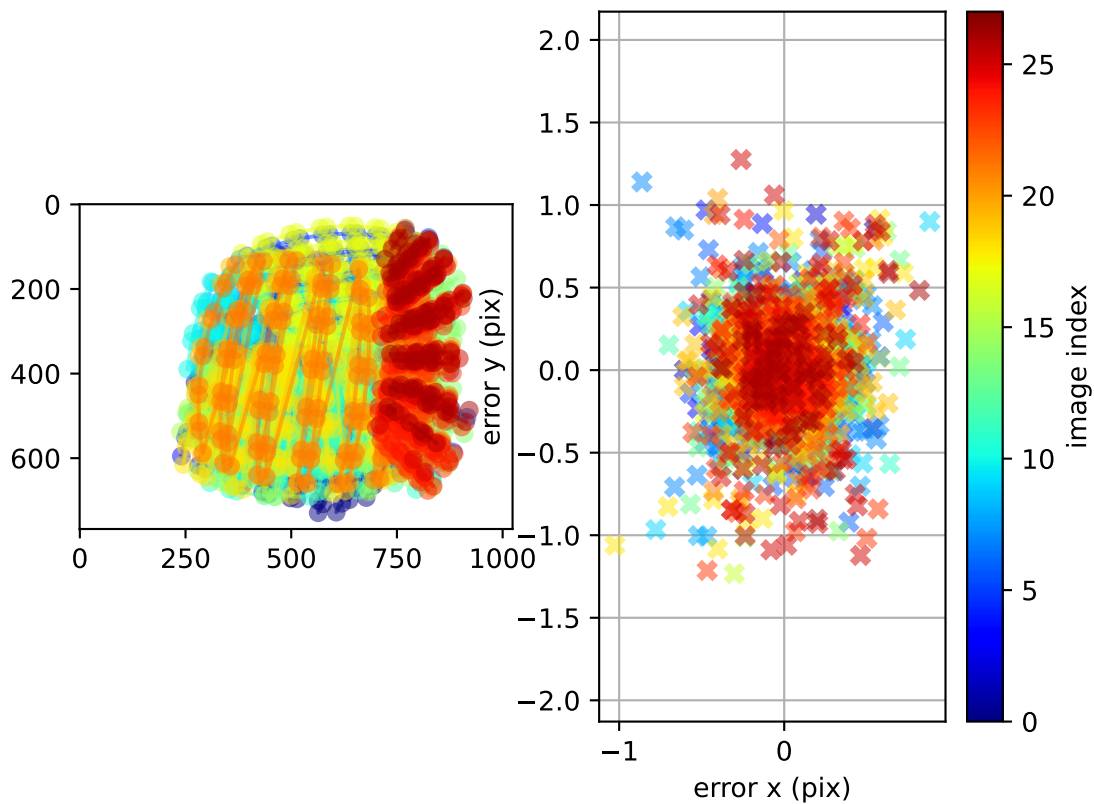
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

