

Calibration results

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Camera-system parameters:

cam0 (/usb_cam/image_raw):

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

distortion: [-0.18437422 0.01612758 -0.00113041 0.00020777] +- [0.00306927 0.00735407 0.0068055 0.00212436]

projection: [604.3598765 605.50588627 982.12867105 545.22099235] +- [0.52940308 0.56997165 0.18454997
0.30796473]

reprojection error: [0.000003, -0.000001] +- [0.675947, 0.638160]

Target configuration

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Type: aprilgrid

Tags:

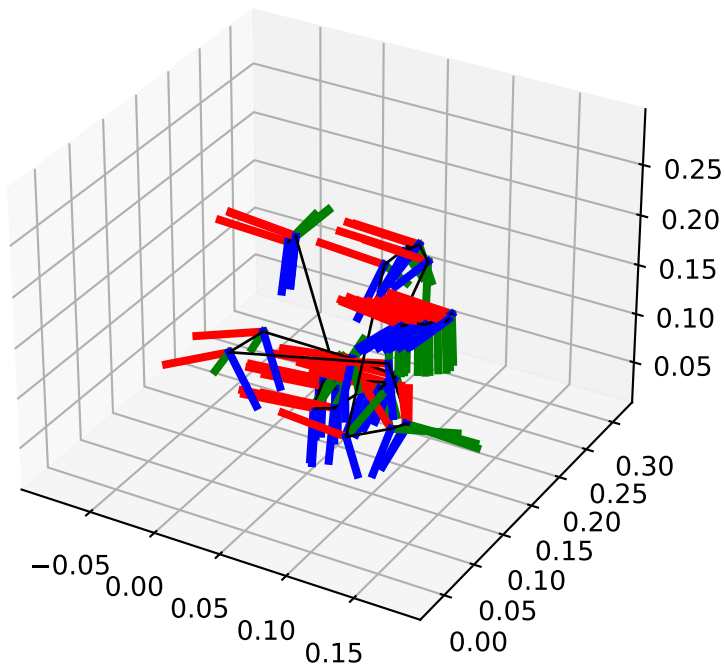
Rows: 6

Cols: 6

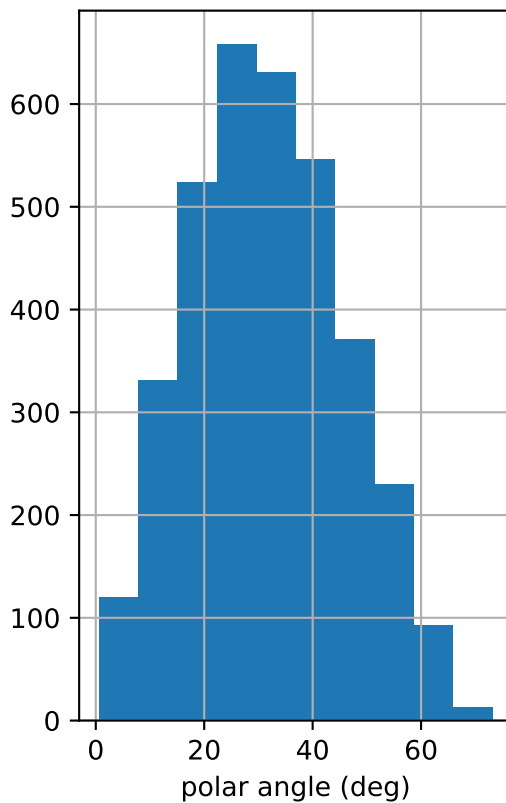
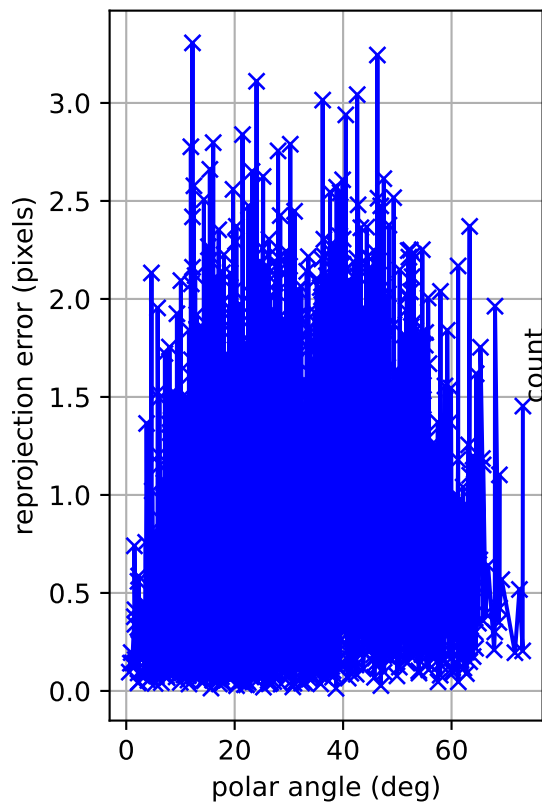
Size: 0.022 [m]

Spacing 0.006599999999999999 [m]

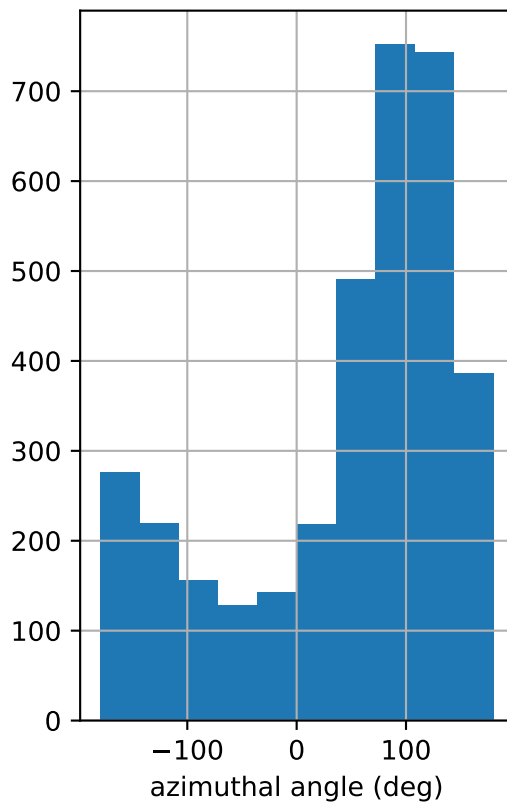
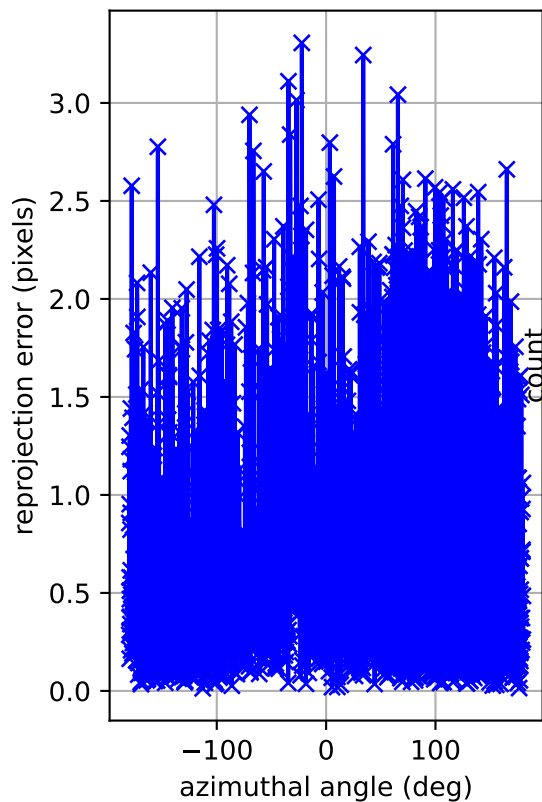
cam0: estimated poses



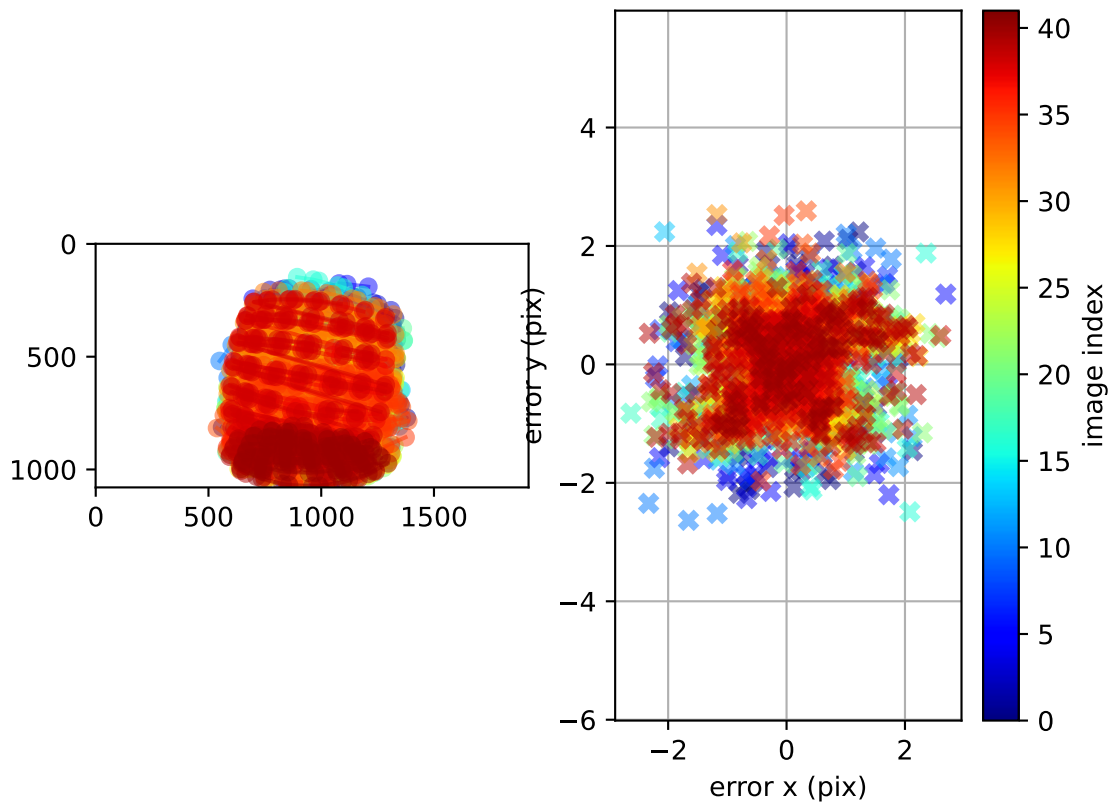
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

