

Calibration results

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Camera-system parameters:

cam0 (/camera/left/image_raw_4hz):

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

distortion: [-0.405603 0.15310488 -0.00068865 -0.00042327] +- [0.00441351 0.00585591 0.00076574 0.00098317]

projection: [459.53088735 459.99193671 394.76604955 247.4833917] +- [1.74603391 1.7590682 2.79497995 1.95602552]

reprojection error: [0.000001, 0.000000] +- [0.100426, 0.087585]

Target configuration

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Type: checkerboard

Rows

Count: 5

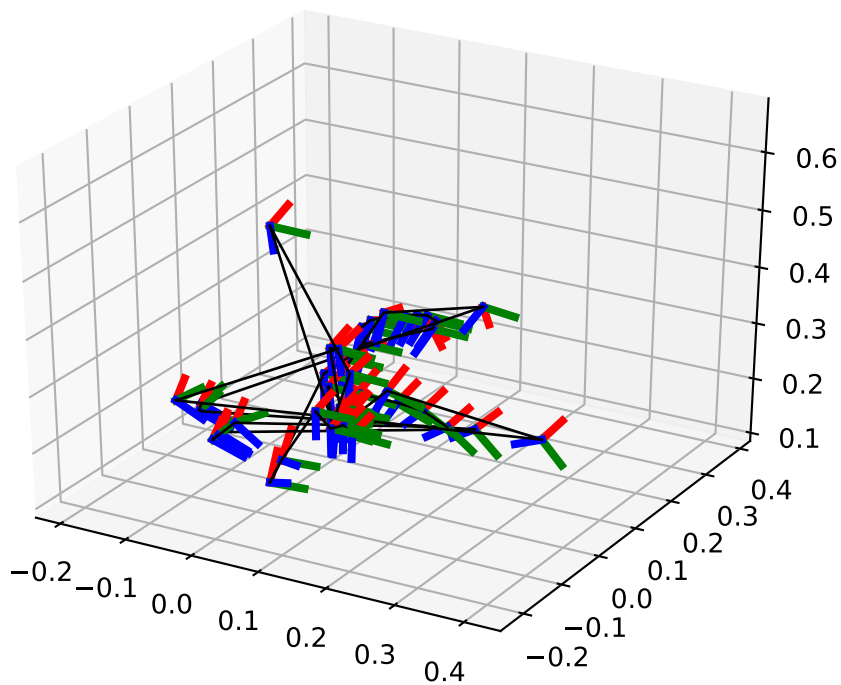
Distance: 0.03 [m]

Cols

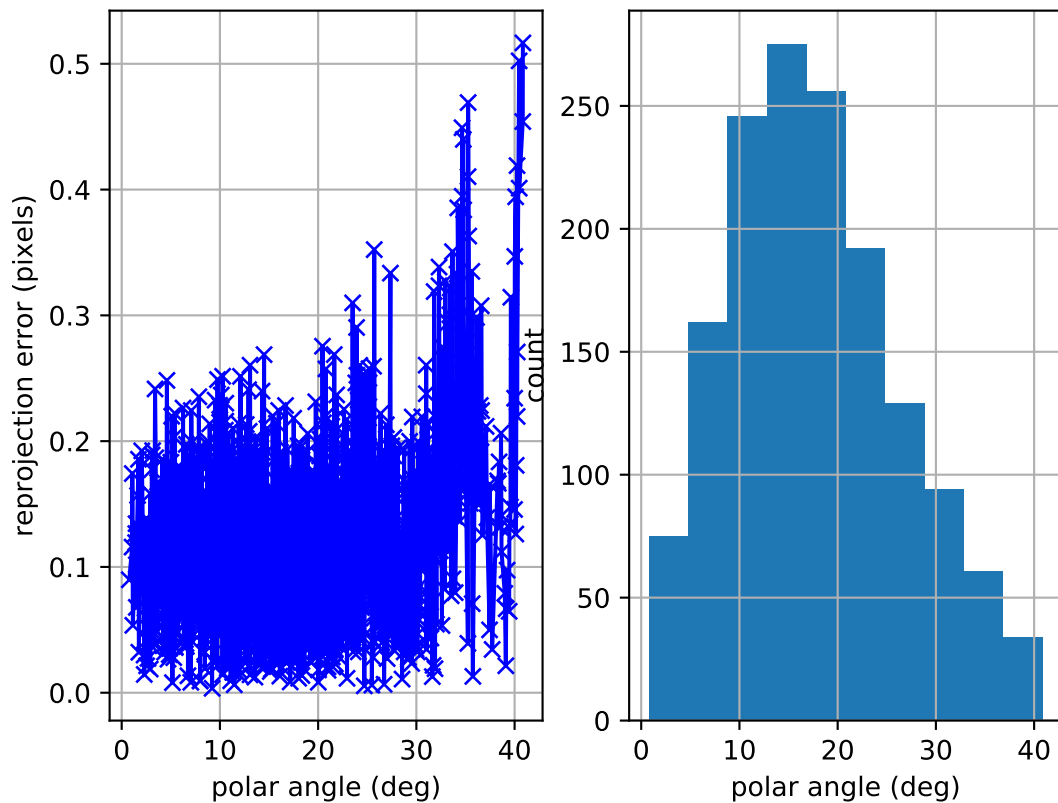
Count: 7

Distance: 0.03 [m]

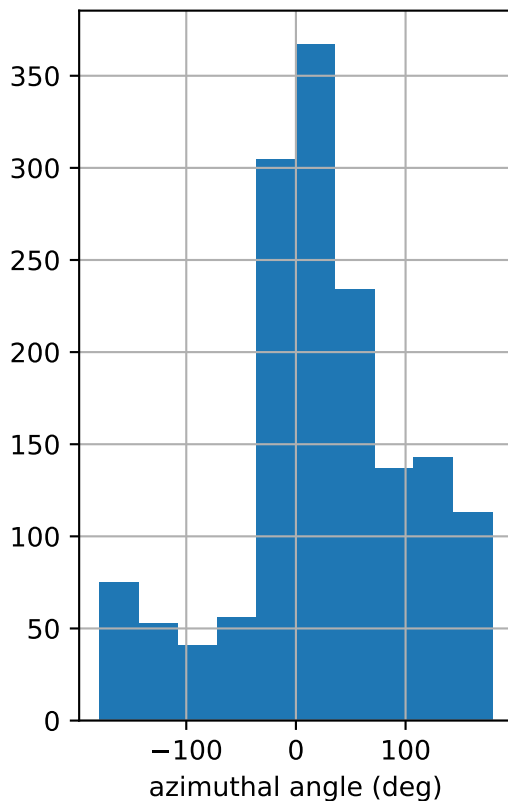
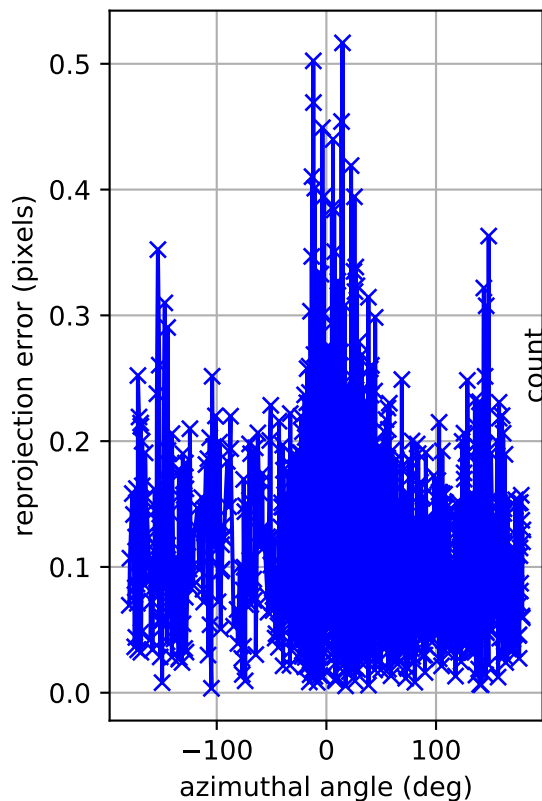
cam0: estimated poses



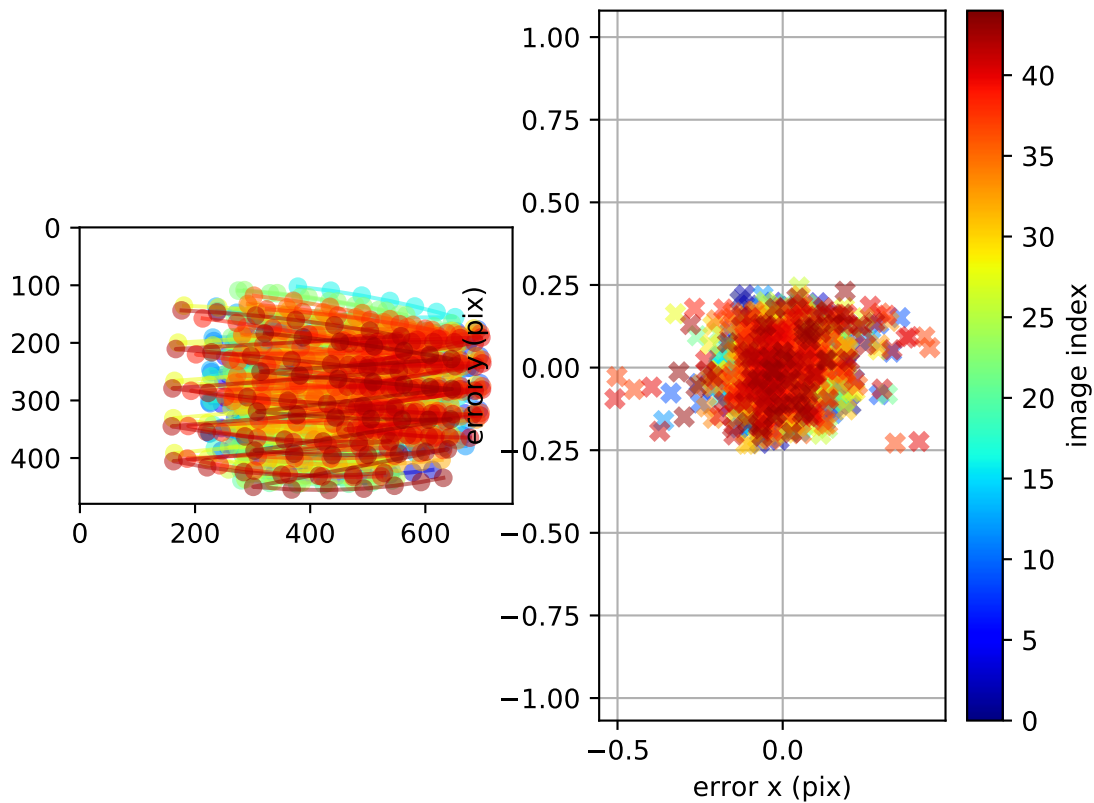
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

