

Calibration results

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Camera-system parameters:

cam0 (/camera/image_raw):

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

distortion: [0.06222026 -0.07000556 0.08568694 -0.03904687] +- [0.01246854 0.042384 0.05745774 0.02644888]

projection: [285.5616793 380.23989862 313.30205021 224.6833171] +- [0.90666893 1.21640807 1.14056652
1.10163684]

reprojection error: [0.000000, -0.000000] +- [0.258091, 0.244071]

Target configuration

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Type: checkerboard

Rows

Count: 6

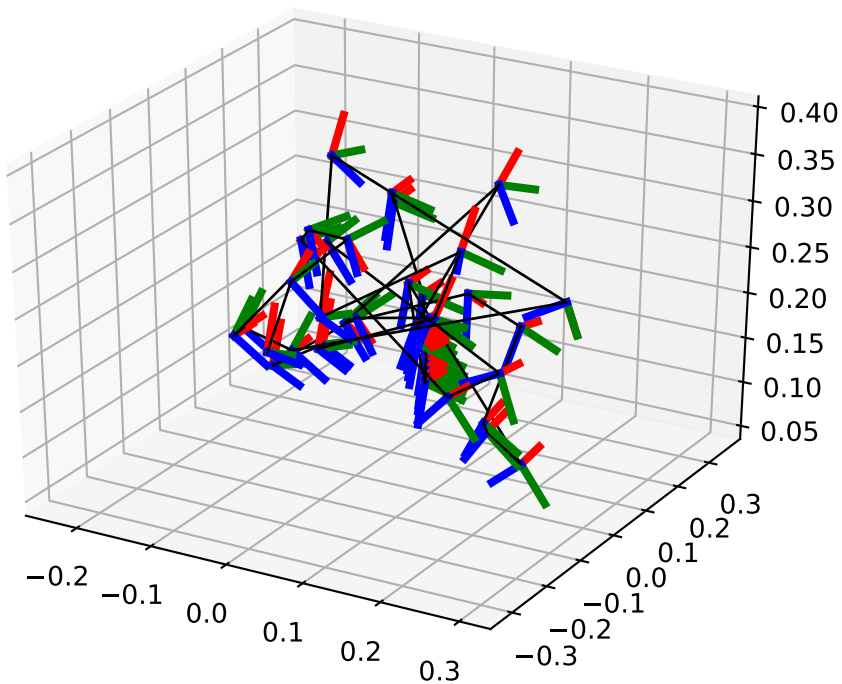
Distance: 0.022 [m]

Cols

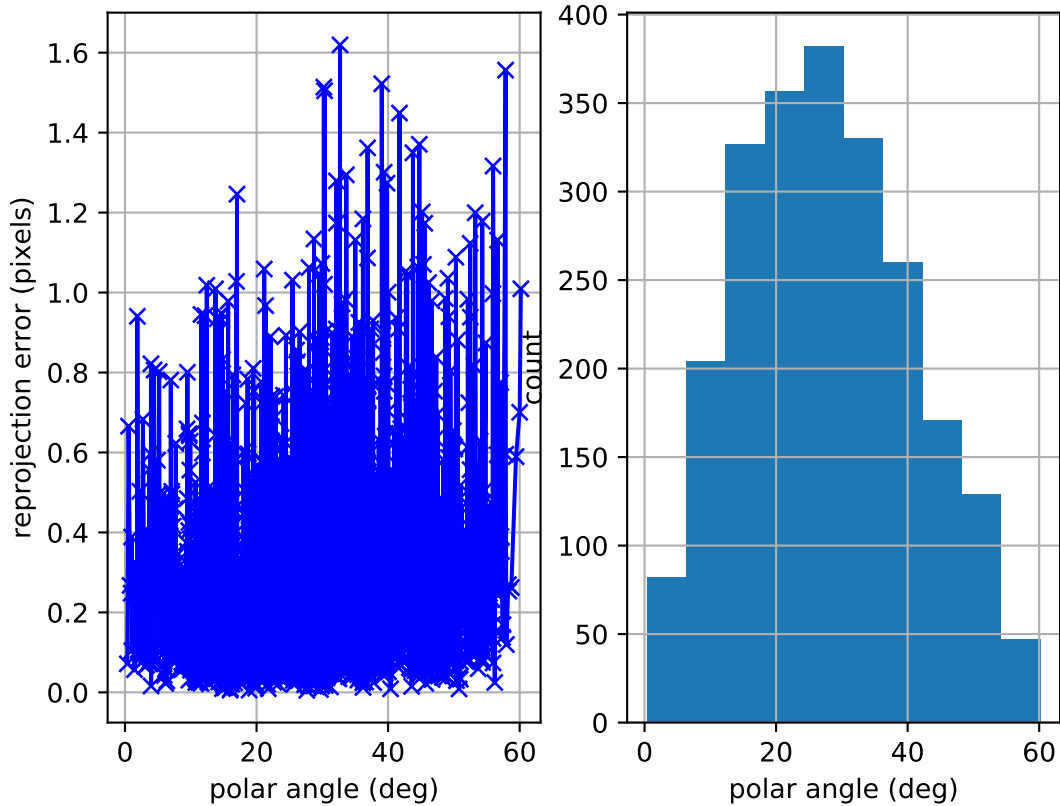
Count: 9

Distance: 0.022 [m]

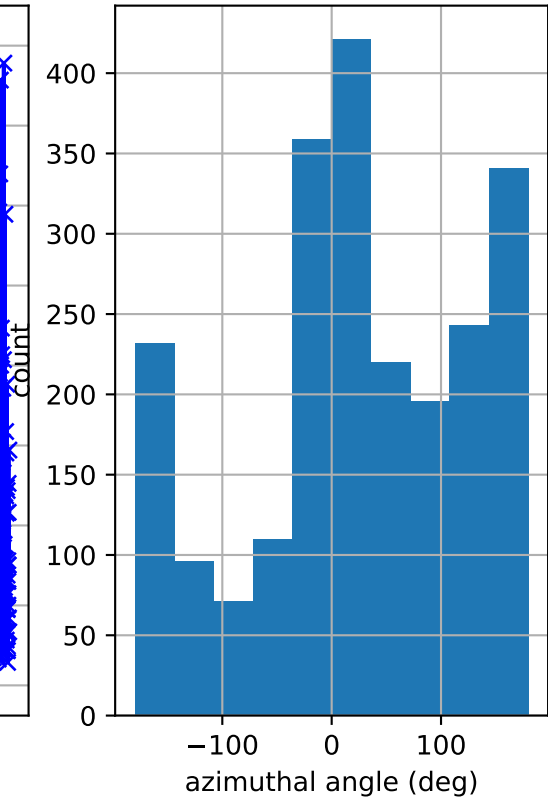
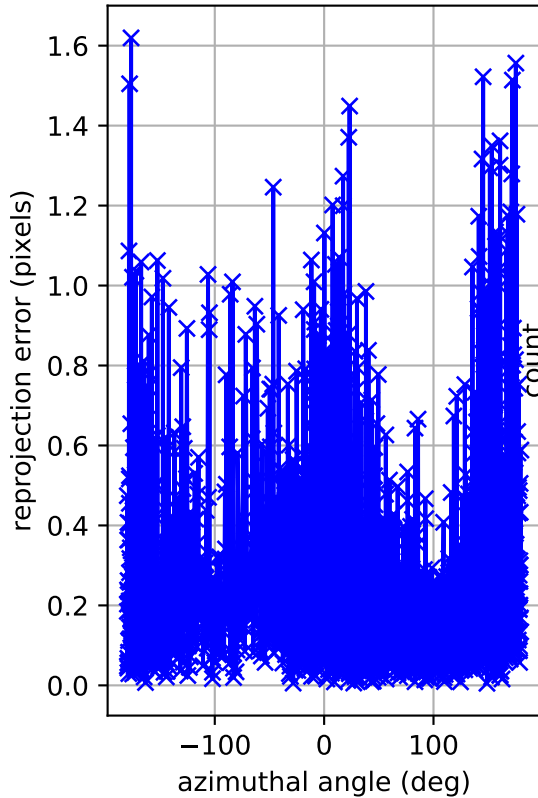
cam0: estimated poses



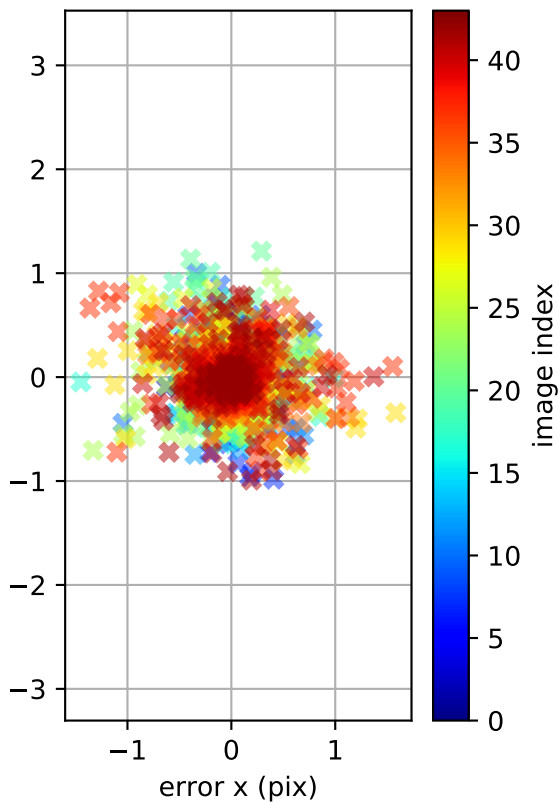
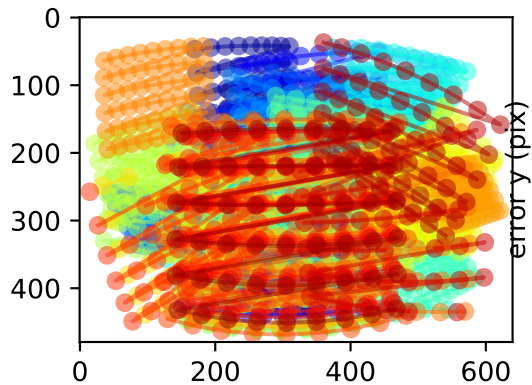
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

