

## Calibration results

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### Camera-system parameters:

cam0 (/camera/mono\_left/image\_raw):

type: <class 'aslam\_cv.libaslam\_cv\_python.DistortedPinholeCameraGeometry'>

distortion: [-0.21258817 0.05930028 0.00035036 0.0002549 ] +- [0.00068603 0.00058014 0.00009633 0.00008951]

projection: [1189.80055884 1185.23374923 947.44718877 597.35293603] +- [1.5443973 1.52573774 1.60815075 1.84298475]

reprojection error: [0.000006, 0.000003] +- [0.555972, 0.461356]

## Target configuration

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Type: aprilgrid

Tags:

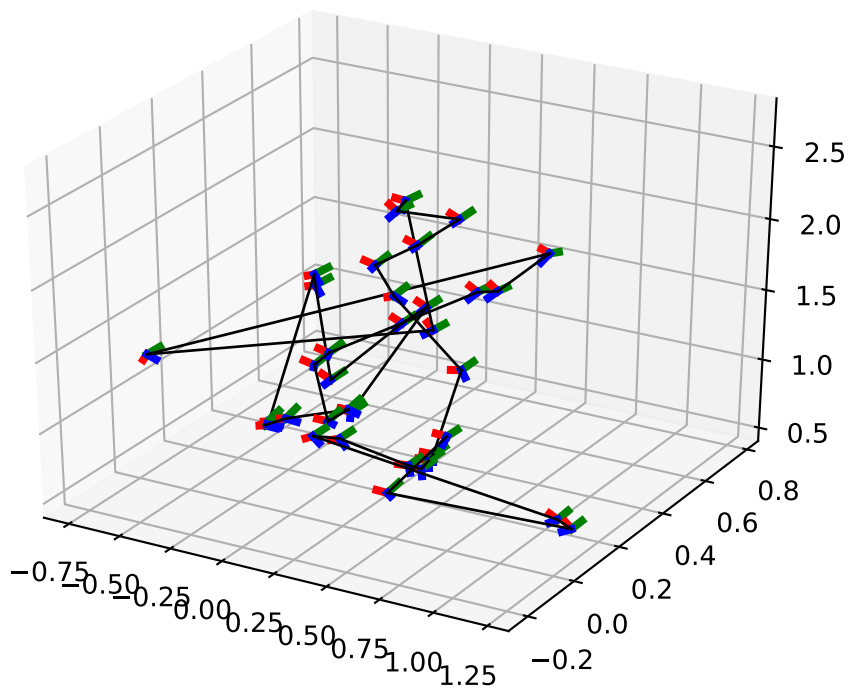
Rows: 6

Cols: 6

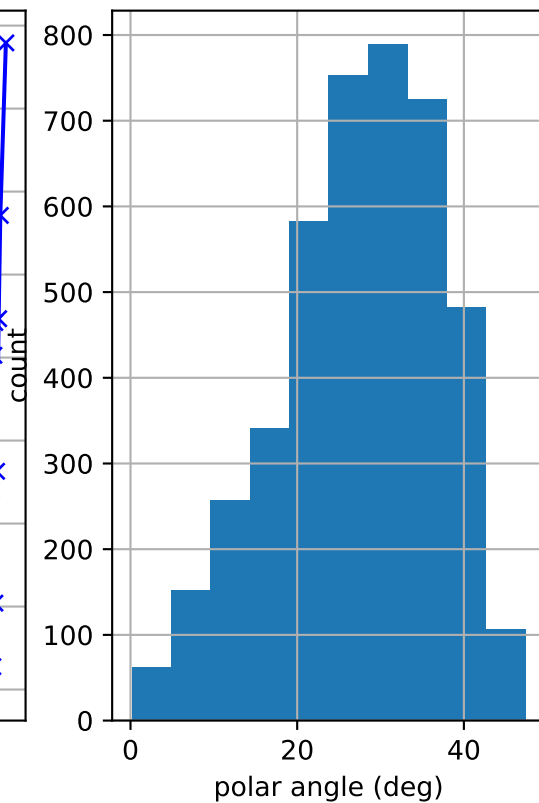
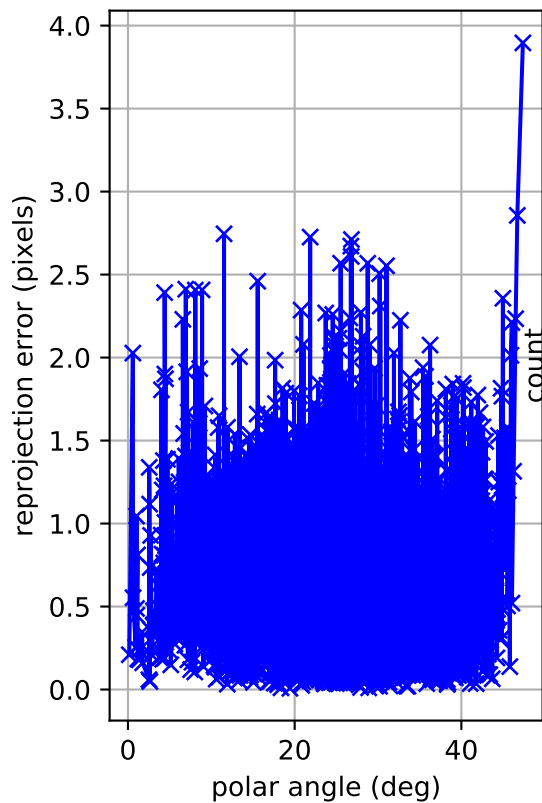
Size: 0.088 [m]

Spacing 0.026399999999999996 [m]

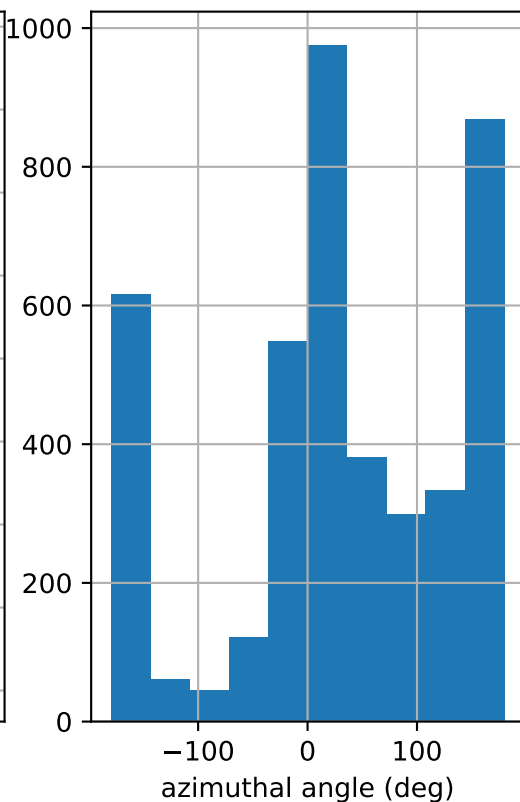
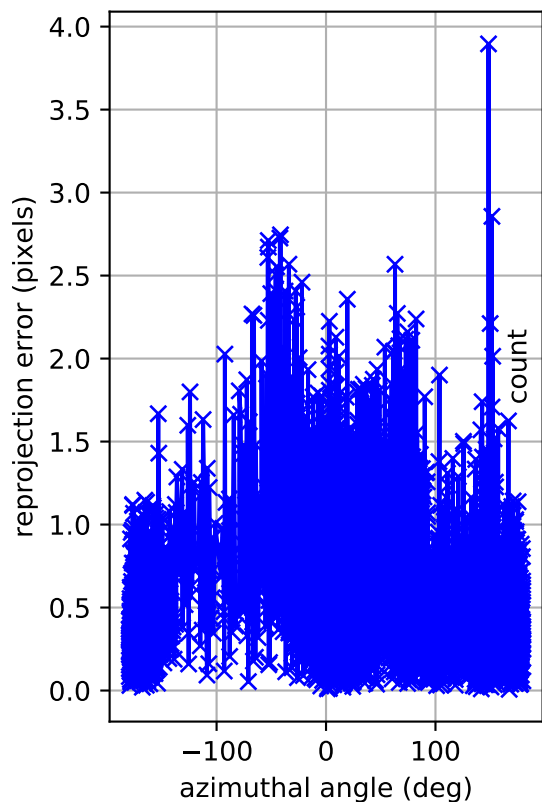
cam0: estimated poses



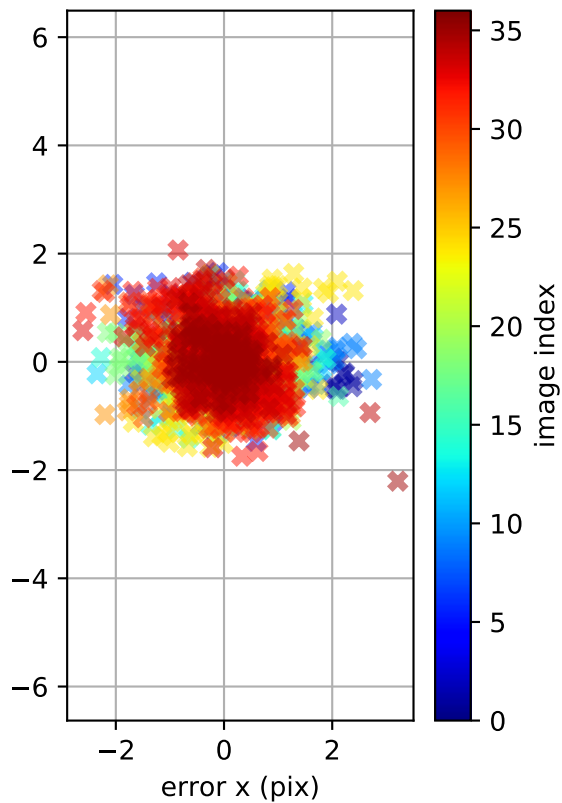
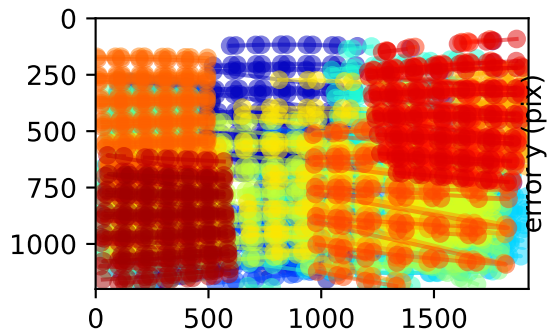
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



# Location of removed outlier corners

cam0

