

## Calibration results

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### Camera-system parameters:

cam0 (/dvs/image\_reconstructed):

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

distortion: [-0.38261608 0.14698837 -0.00143755 -0.00033804] +- [ 0.01411773 0.01302682 0.00208324 0.00140516]

projection: [ 253.84773123 253.88799685 174.01053551 123.19547128] +- [ 6.44614695 6.32733191 2.5508404  
3.63776581]

reprojection error: [0.000001, 0.000000] +- [0.152460, 0.148409]

## Target configuration

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Type: checkerboard

Rows

Count: 8

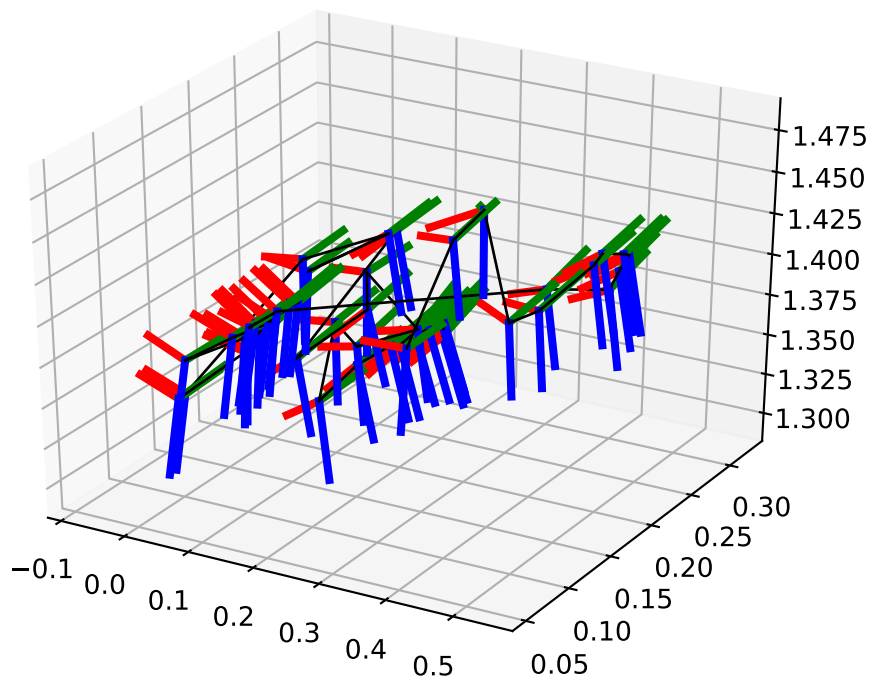
Distance: 0.06 [m]

Cols

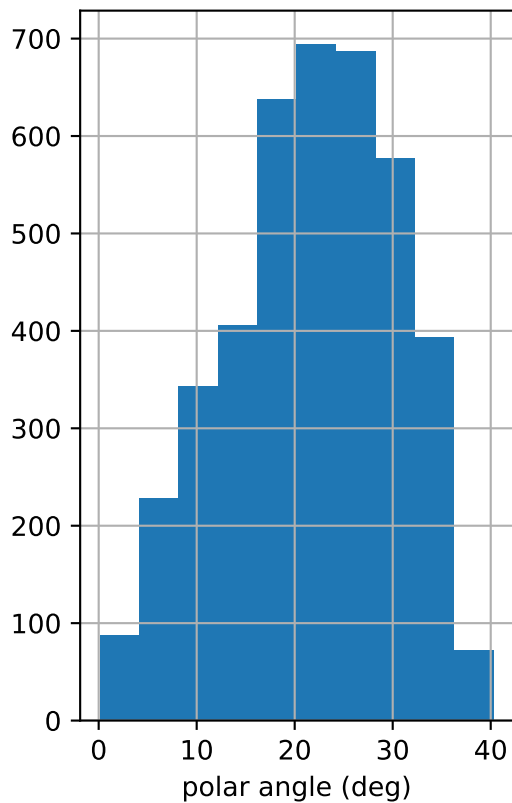
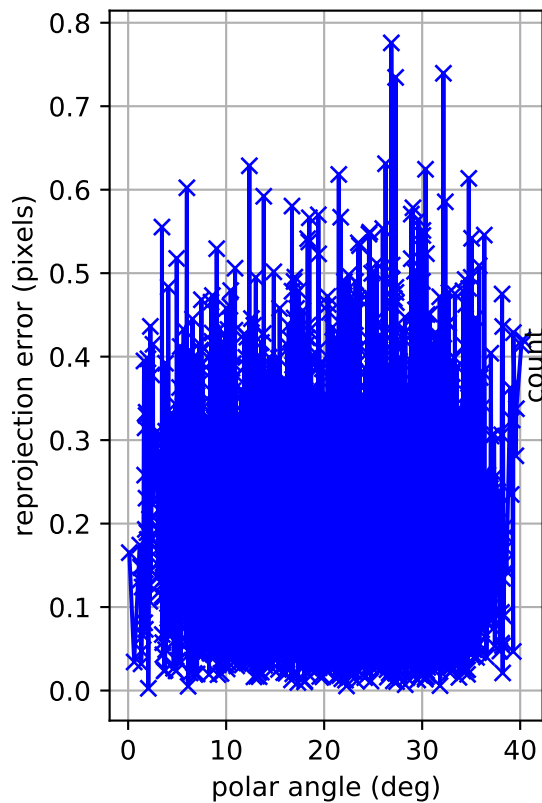
Count: 11

Distance: 0.06 [m]

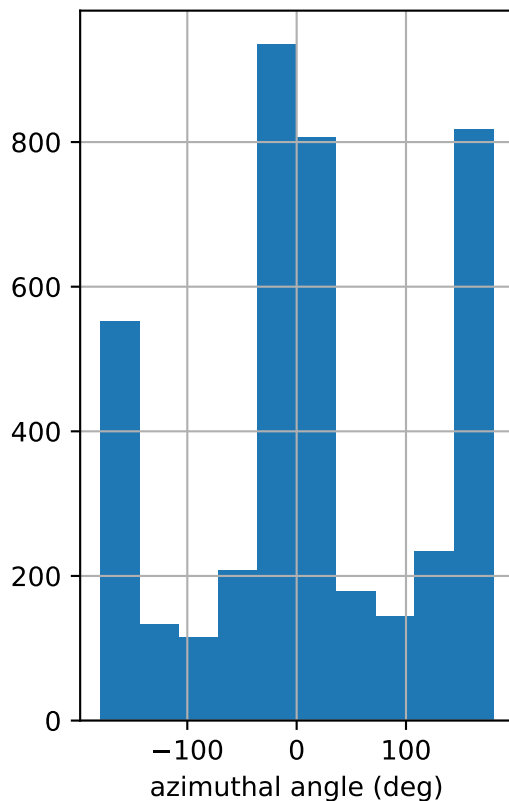
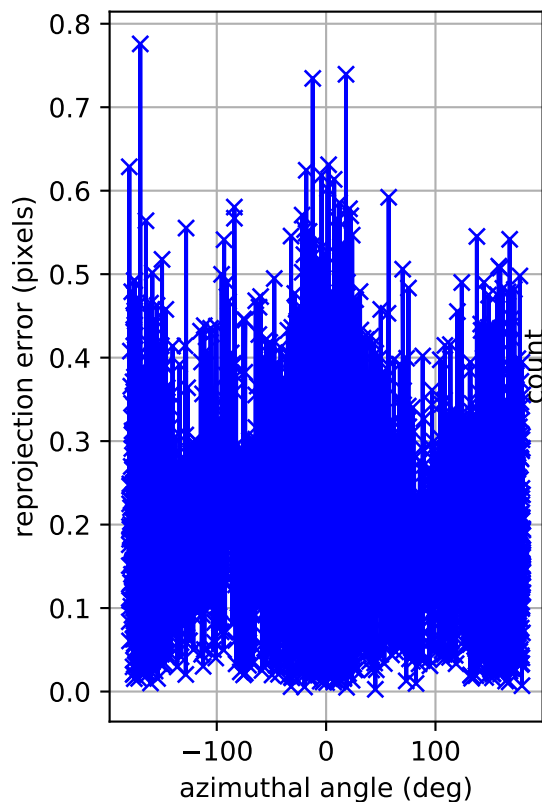
cam0: estimated poses



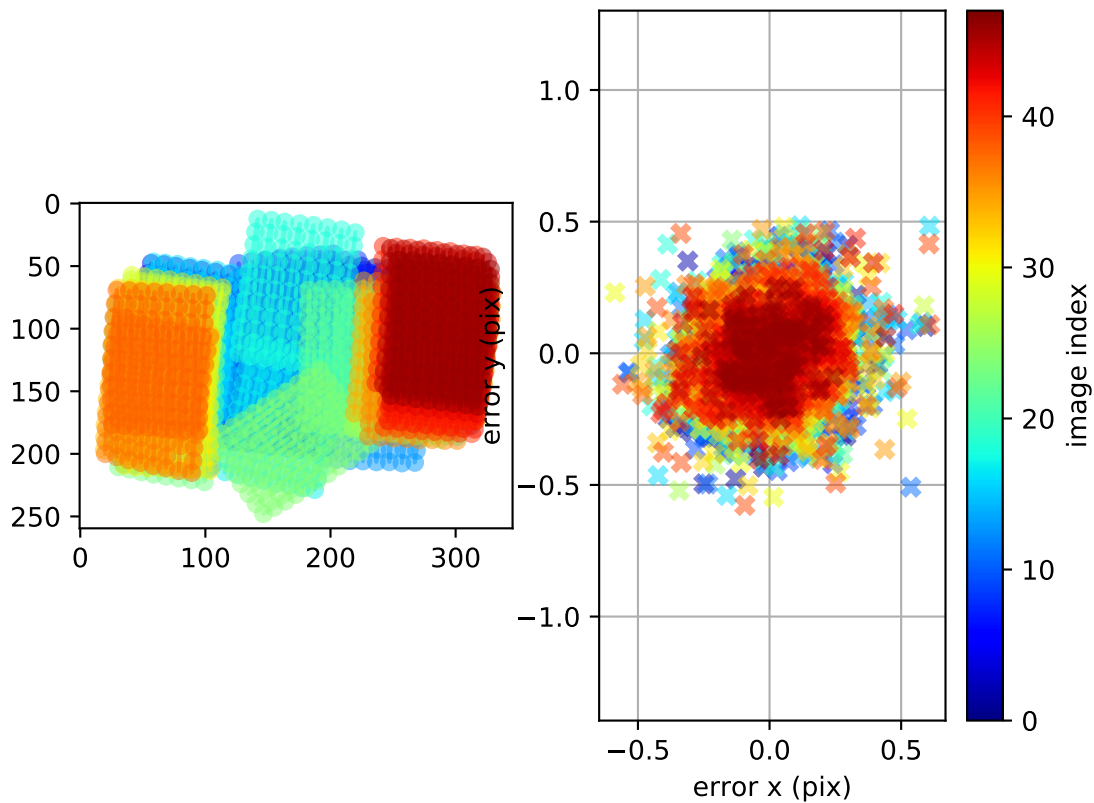
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



Location of removed outlier corners

cam0

