

## Calibration results

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### Camera-system parameters:

cam0 (/color):

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

distortion: [ 0.10701023 -0.22335525 -0.00116392 0.00026251] +- [0.00598452 0.01211564 0.00094609 0.000701 ]

projection: [898.66888041 898.97388089 636.82929468 356.15549674] +- [4.82720857 4.68812121 2.57516109 2.99294541]

reprojection error: [0.000001, 0.000001] +- [0.143981, 0.098633]

## Target configuration

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Type: checkerboard

Rows

Count: 8

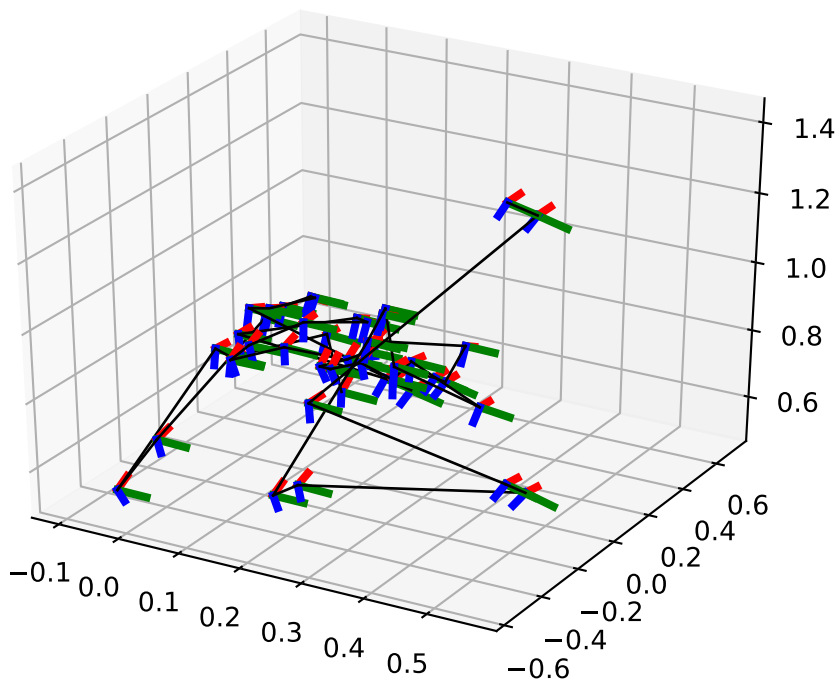
Distance: 0.03 [m]

Cols

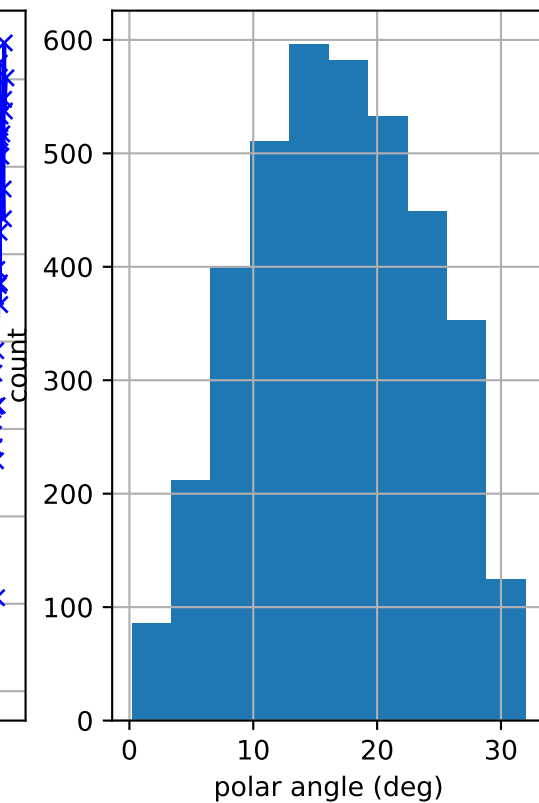
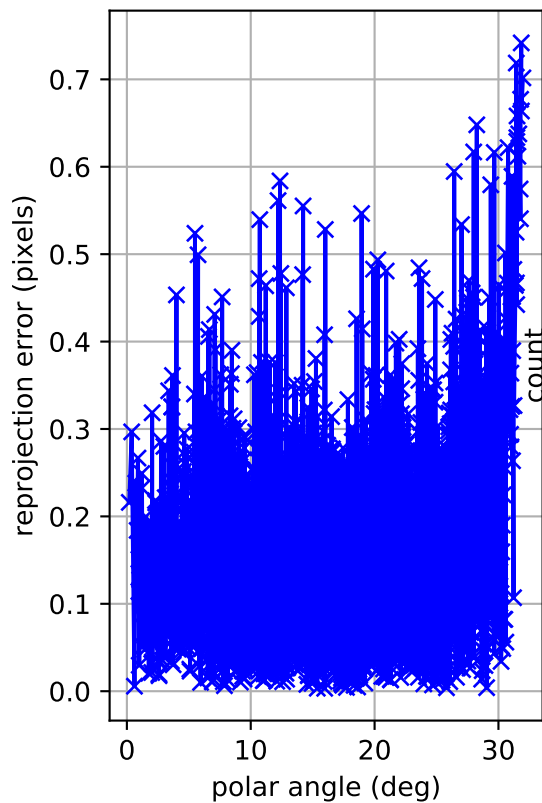
Count: 11

Distance: 0.03 [m]

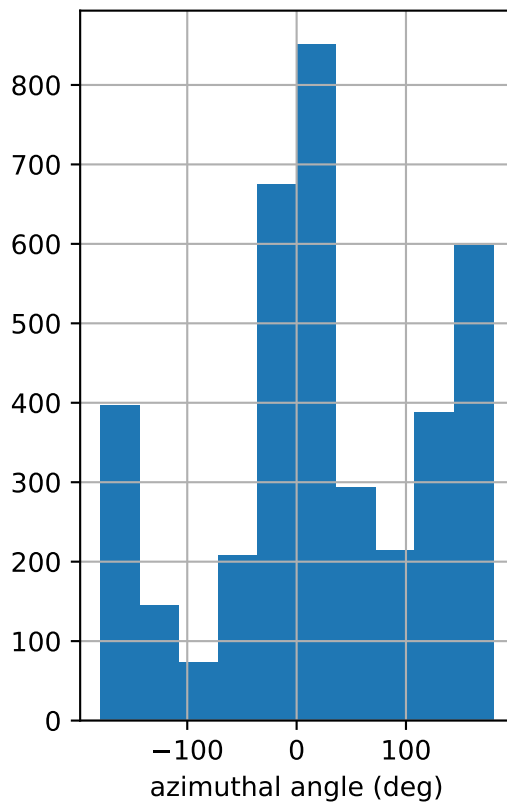
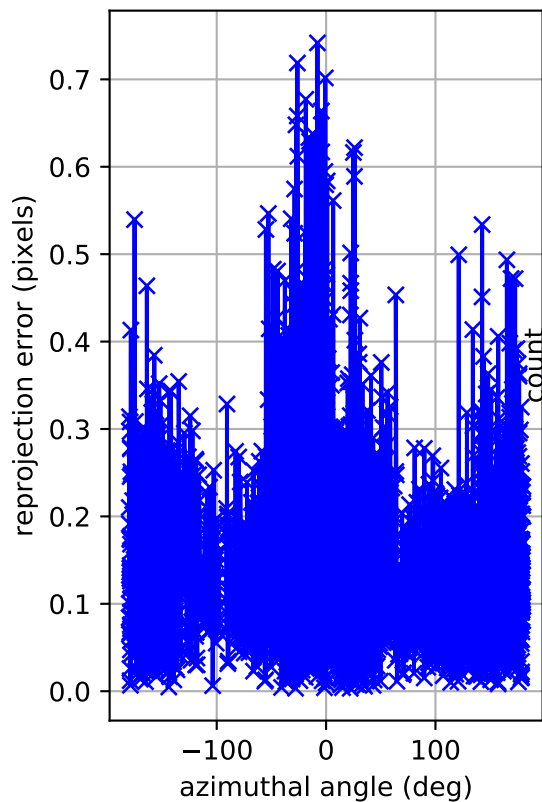
cam0: estimated poses



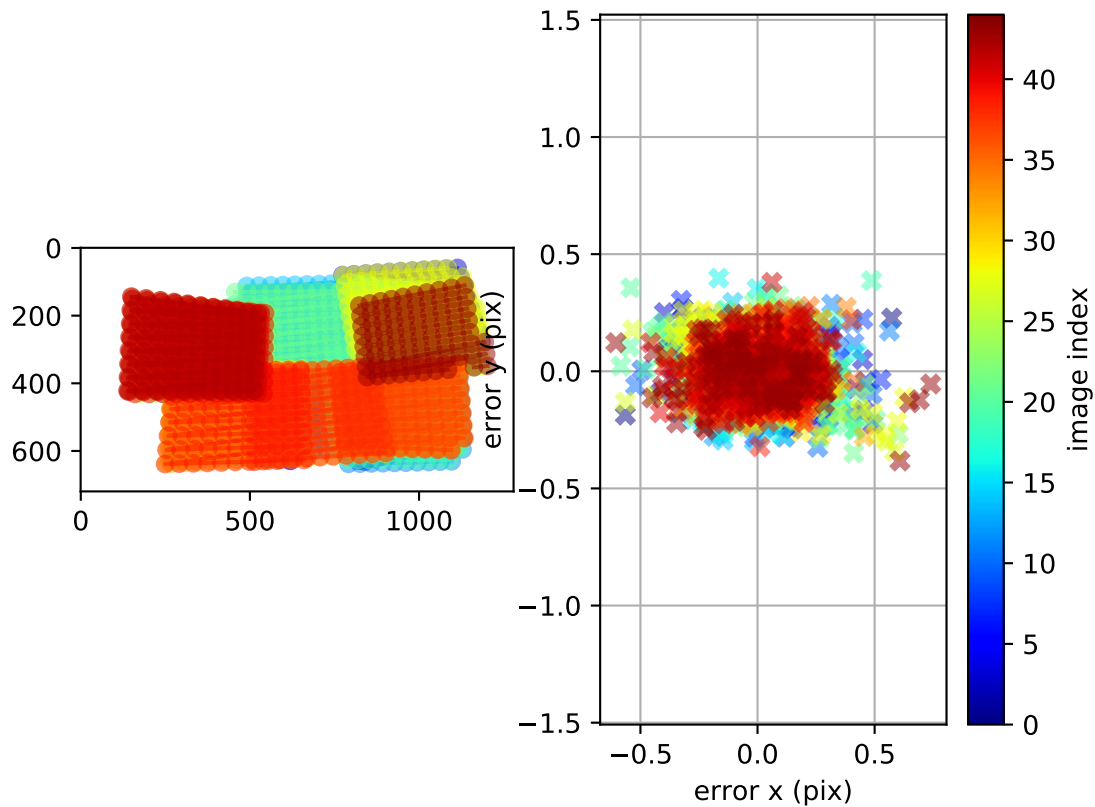
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



### Location of removed outlier corners

