

## Calibration results

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### Camera-system parameters:

cam0 (/feature\_tracker\_imu/camD):

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

distortion: [-0.00784489 0.00880554 0.00054763 -0.00144262] +- [0.00275245 0.0065097 0.00606426 0.00189437]

projection: [562.48358978 562.27580277 641.89072037 432.82602103] +- [0.6754936 0.6288047 0.42007964 0.35266434]

reprojection error: [-0.000007, 0.000006] +- [0.805775, 0.690978]

## Target configuration

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Type: aprilgrid

Tags:

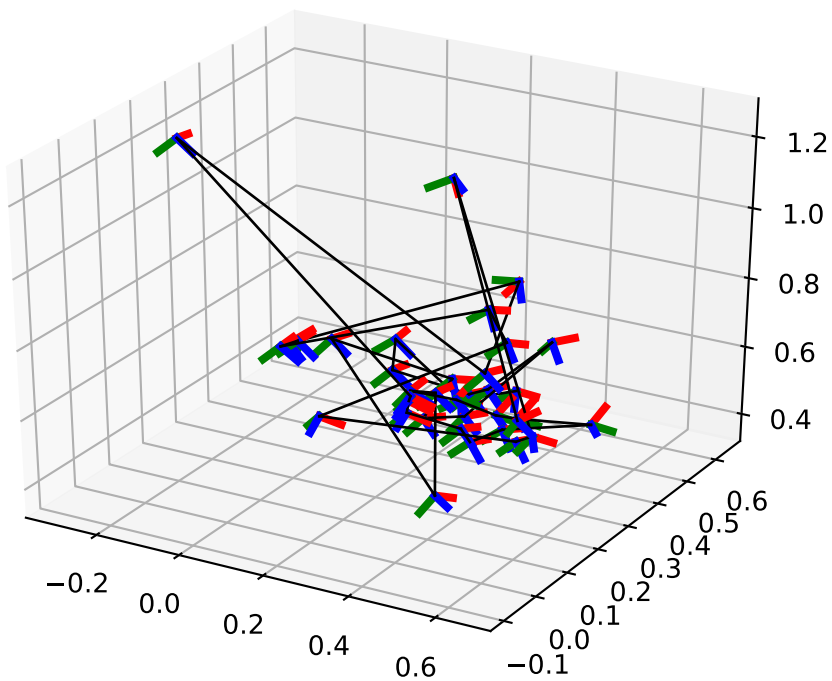
Rows: 6

Cols: 6

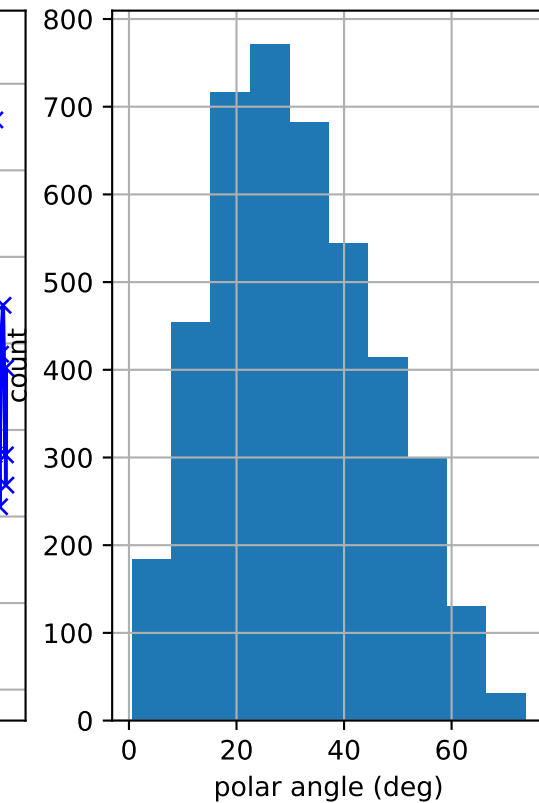
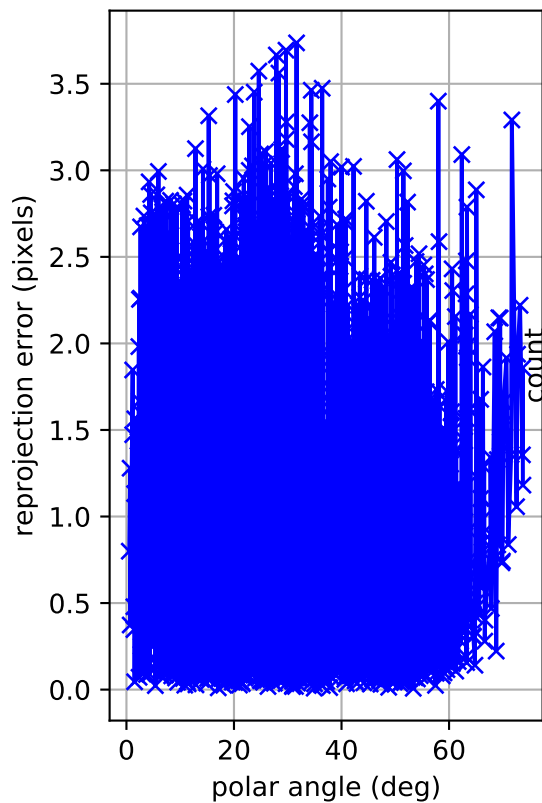
Size: 0.0922 [m]

Spacing 0.02766 [m]

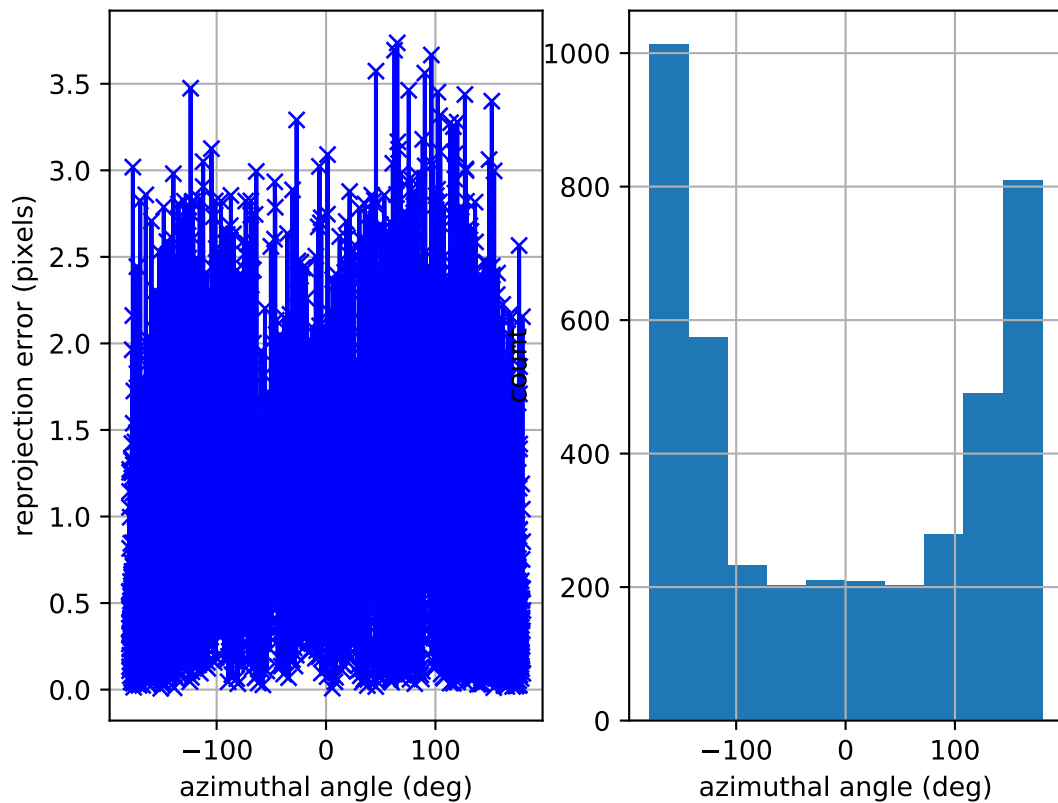
cam0: estimated poses



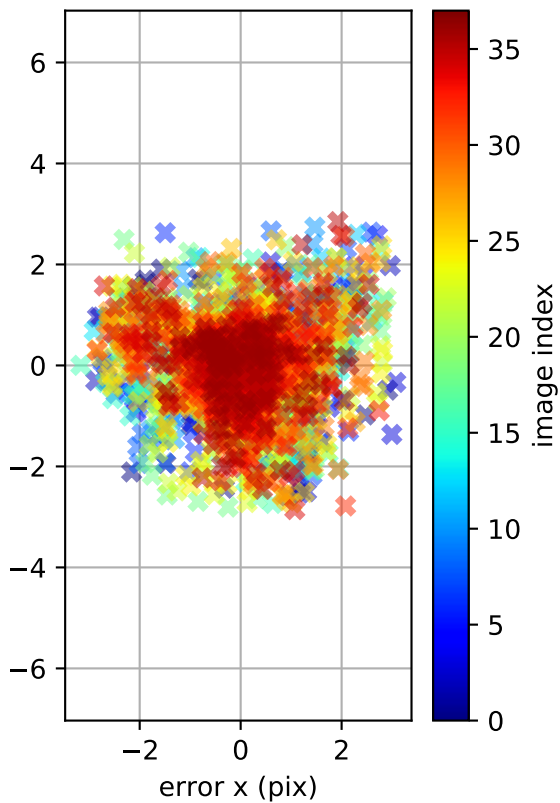
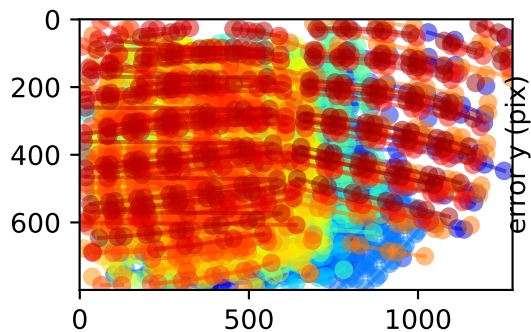
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



# Location of removed outlier corners

