

## Calibration results

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### Camera-system parameters:

cam0 (/camera/left/image\_raw\_4hz):

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

distortion: [-0.41586969 0.17455003 -0.00067328 0.00008043] +- [0.00562985 0.0098624 0.00099513 0.00134228]

projection: [459.65378657 460.05500919 393.07712918 247.58991835] +- [2.73414701 2.62146582 3.41941048 2.52987828]

reprojection error: [-0.000001, -0.000000] +- [0.065892, 0.075811]

## Target configuration

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Type: checkerboard

Rows

Count: 5

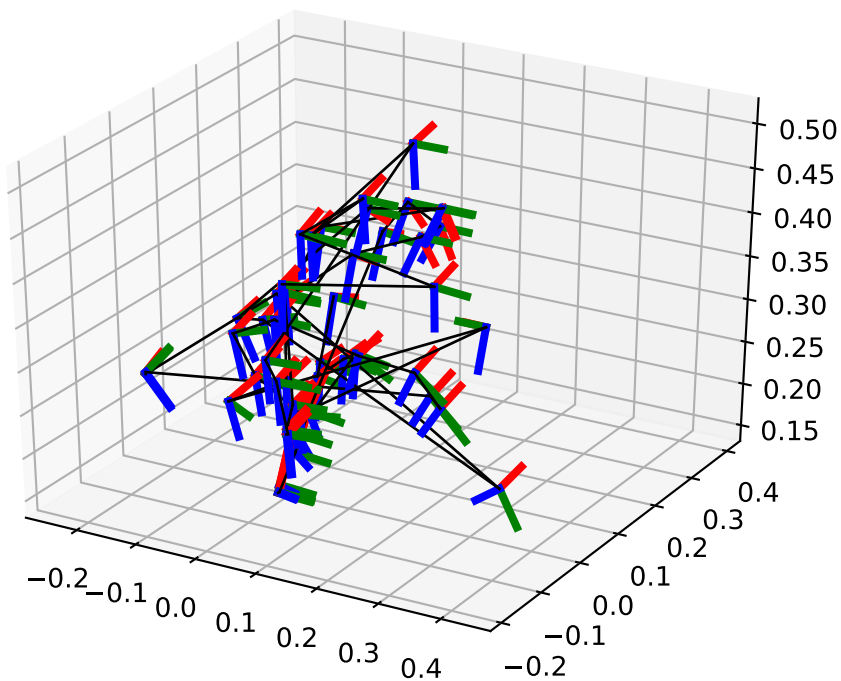
Distance: 0.03 [m]

Cols

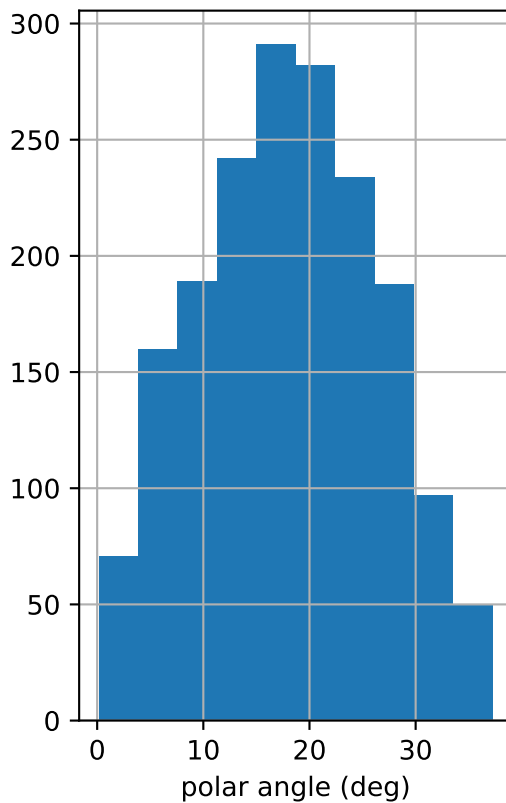
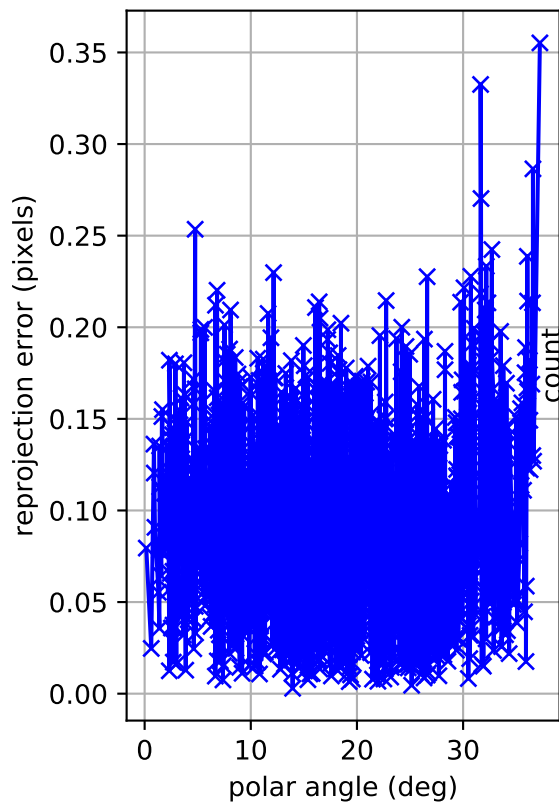
Count: 7

Distance: 0.03 [m]

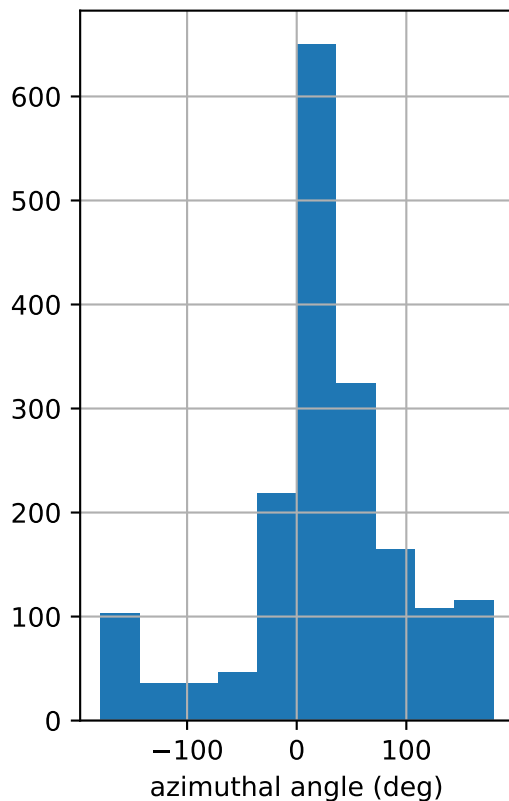
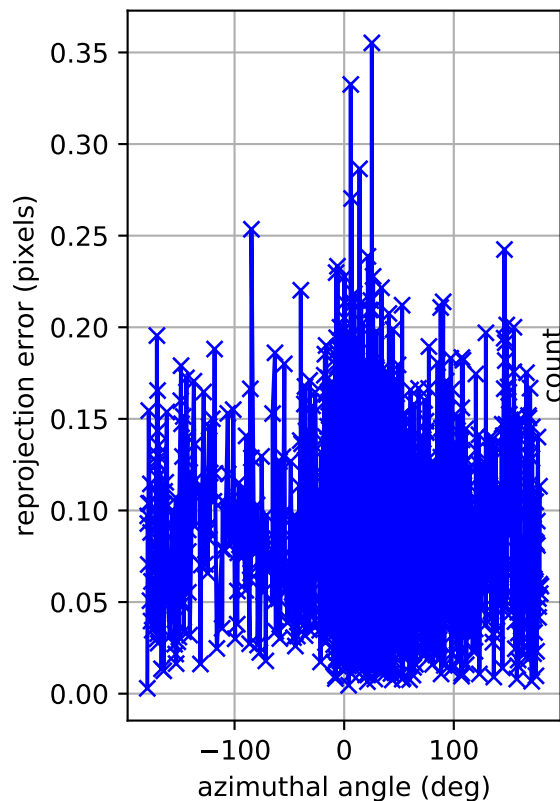
cam0: estimated poses



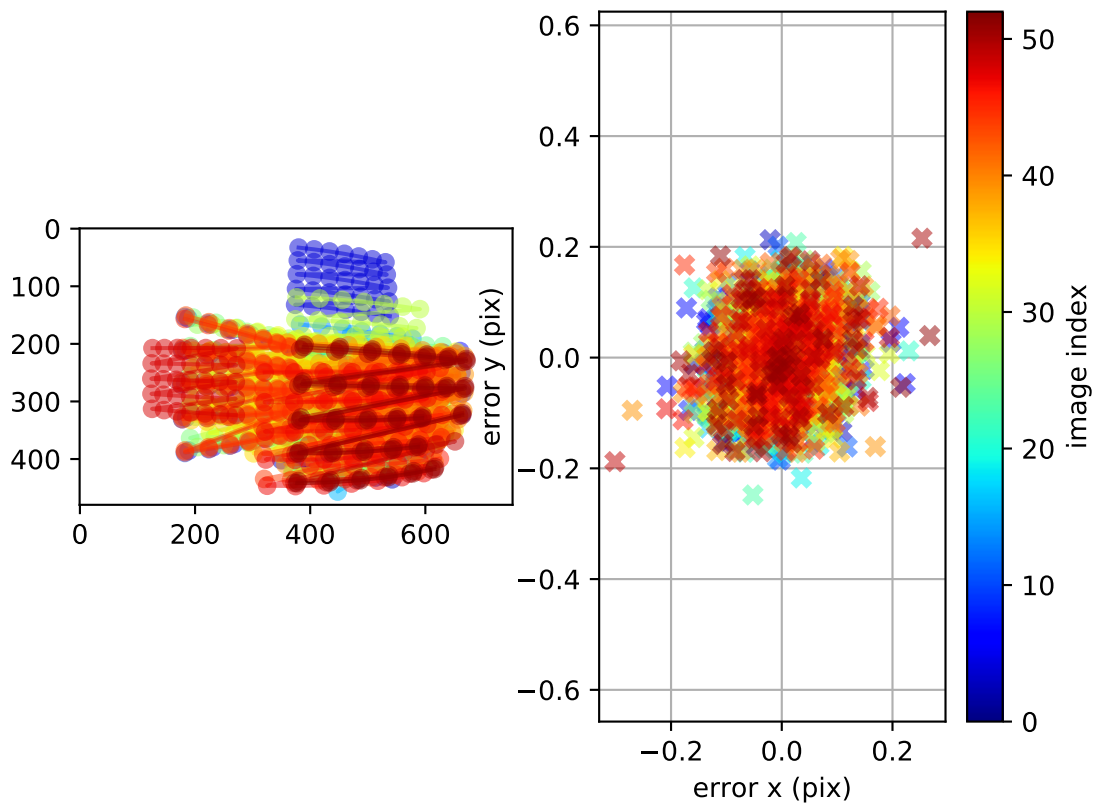
cam0: polar error



cam0: azimuthal error



cam0: reprojection errors



# Location of removed outlier corners

