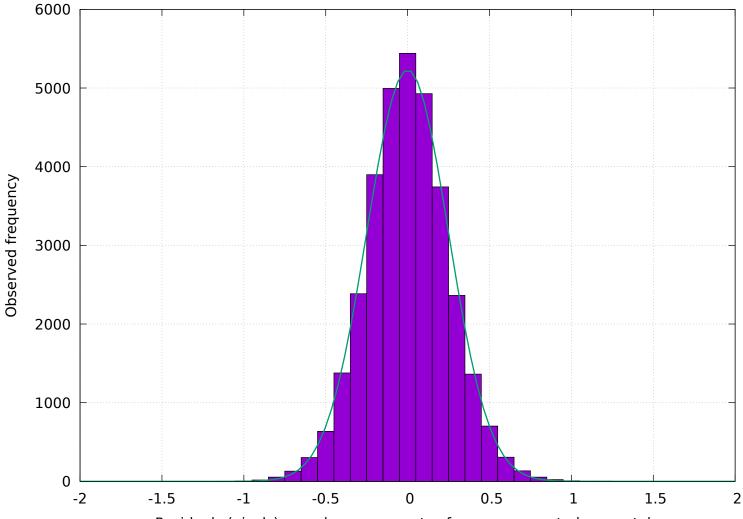
Distribution of fitted residuals and a gaussian fit for all the cameras



Residuals (pixels). x and y components of error are counted separately