Calibration results
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Camera-system parameters:
cam0 (/camera/camera/infra1/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.03419681 0.02297372 0.00197395 0.00102166] +- [0.00174001 0.00247925 0.00032458 0.00037165]
projection: [382.16267863 380.87123084 327.20539971 241.25522356] +- [0.34073548 0.3518688 0.35928527
0.33479341]
reprojection error: [0.000019, -0.000000] +- [0.582762, 0.775282]

cam1 (/camera/camera/infra2/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.03672014 -0.00187627 0.00259978 0.00148124] +- [0.00154122 0.00179887 0.00031942 0.00037917]
projection: [382.30970478 381.06337026 320.26750117 241.70101347] +- [0.34297283 0.35226845 0.38858593
0.35361654]
reprojection error: [-0.000020, 0.000000] +- [0.546491, 0.720413]

baseline T_1_0:
q: [-0.00122155 -0.00915646 -0.00039766 0.99995725] +- [0.00090117 0.00112832 0.00012984]
t: [-0.04985933 -0.00005484 0.00036374] +- [0.00002211 0.00002055 0.00006851]

Target configuration
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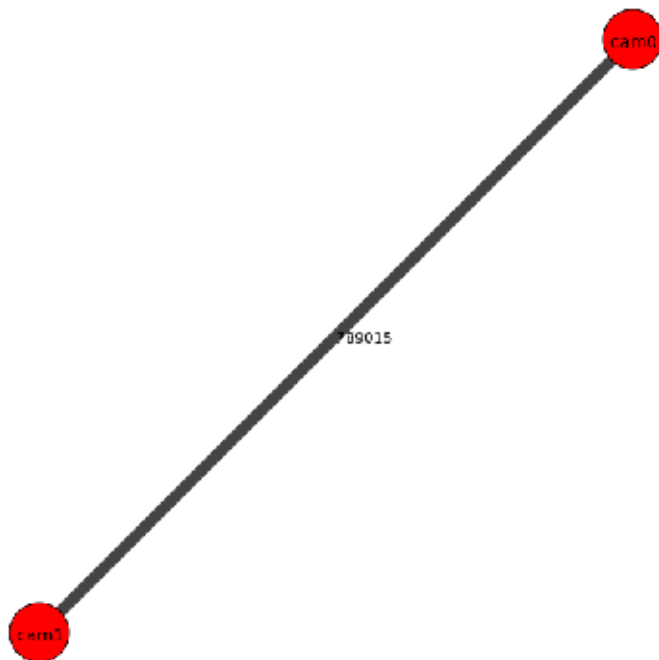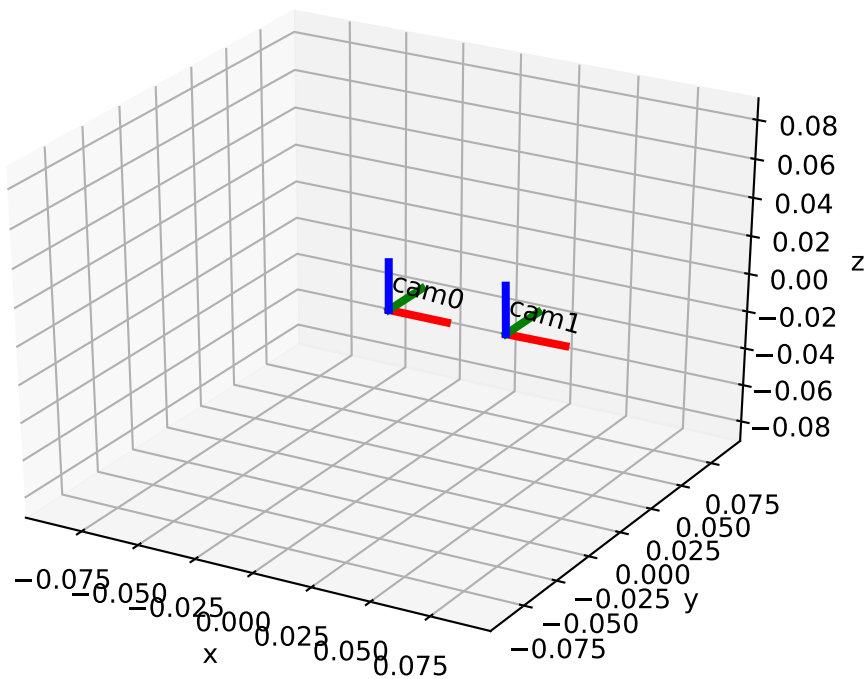
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0205 [m]
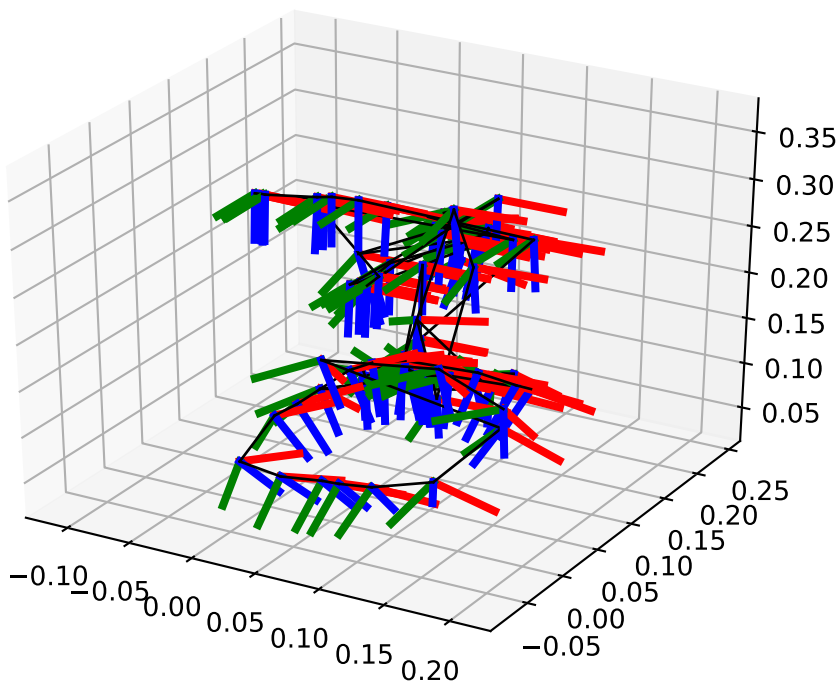Spacing 0.00630006 [m]

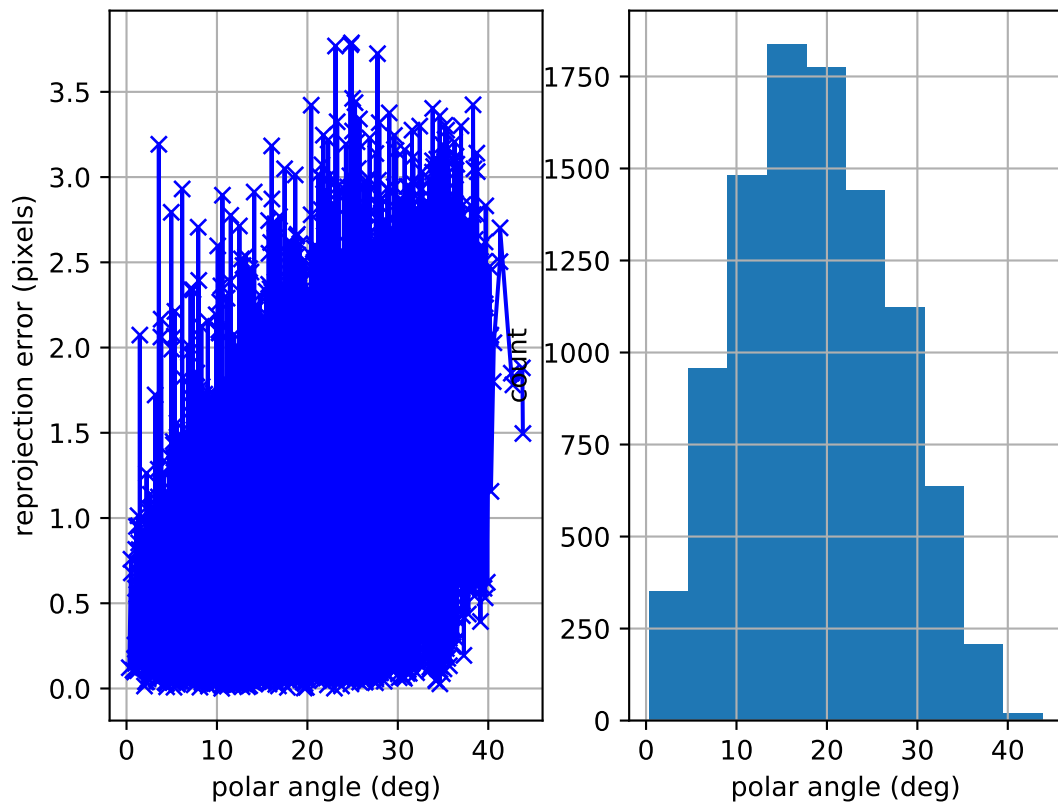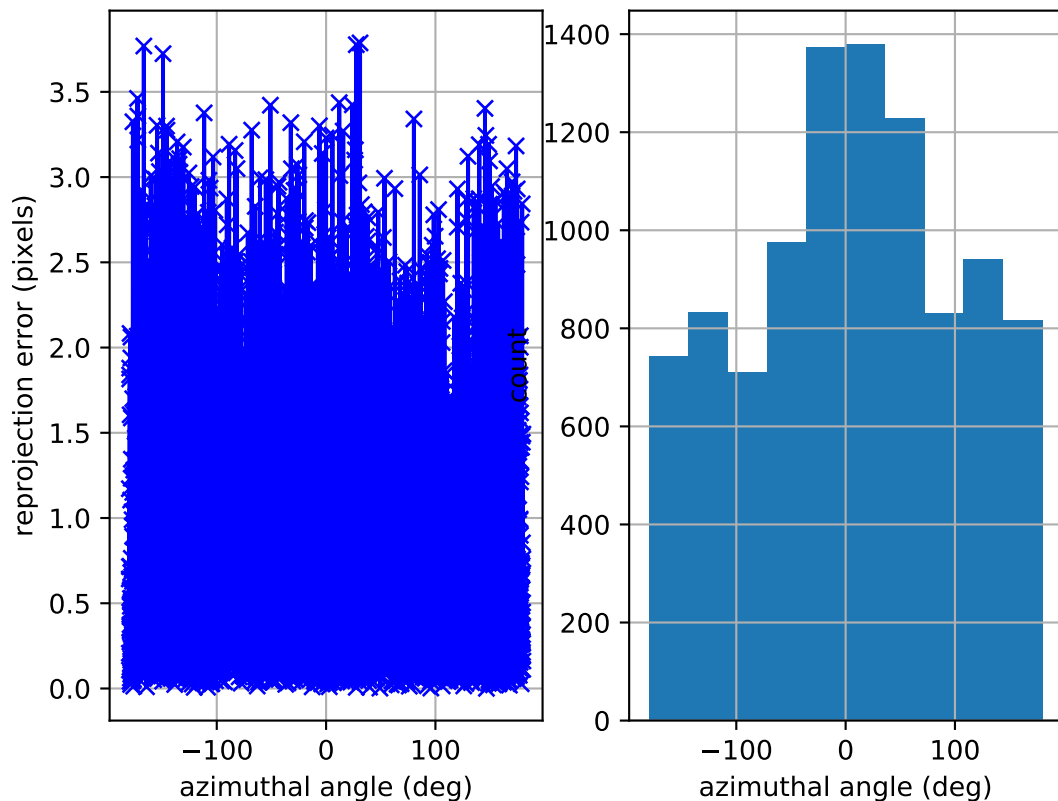Inter-camera observations graph (edge weight=#mutual obs.)
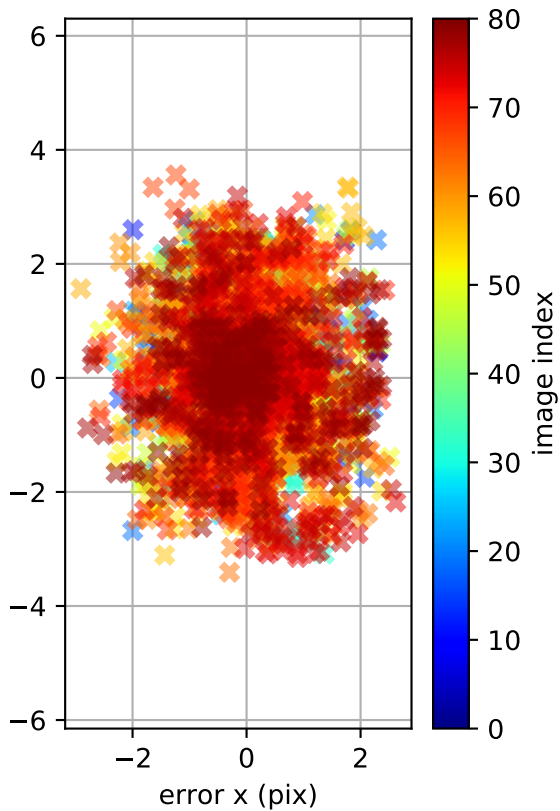
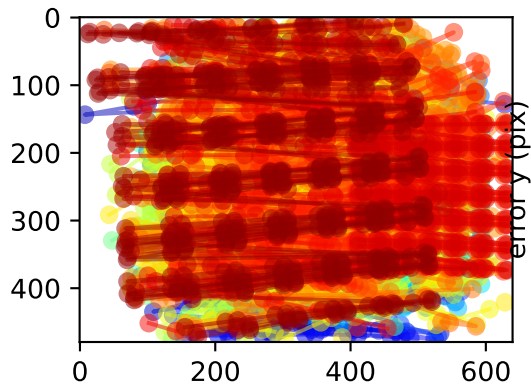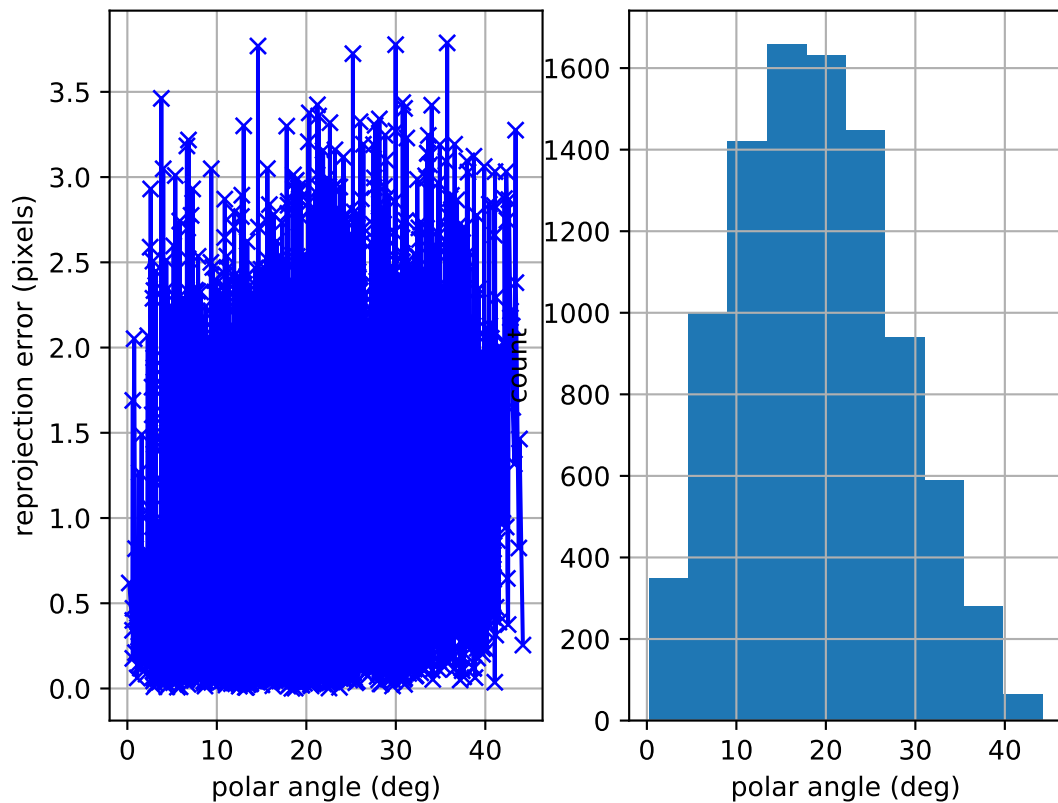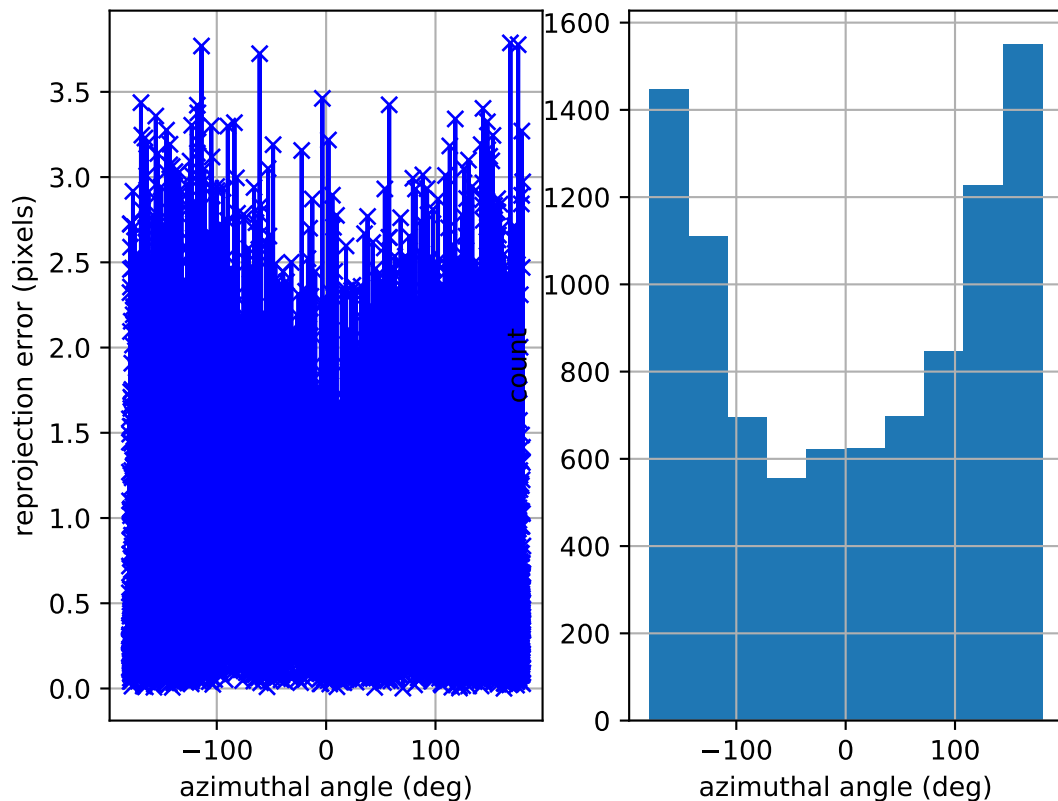camera system

cam0: estimated poses

cam0: polar error
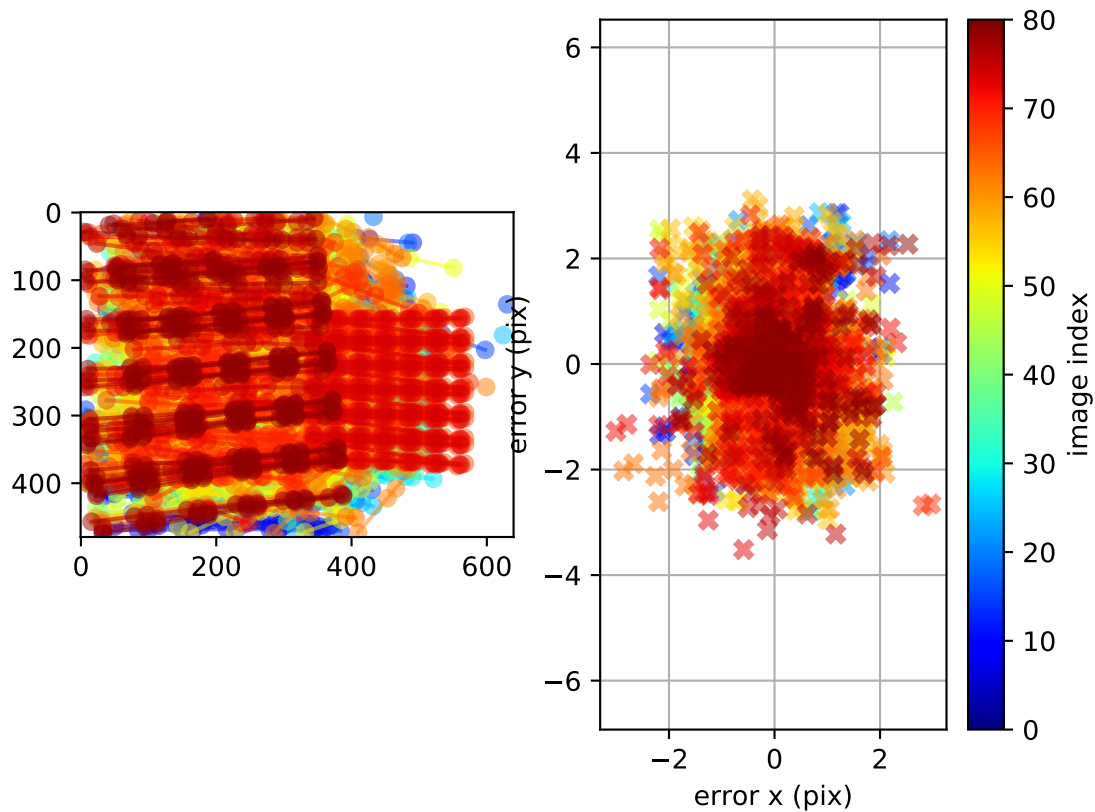
cam0: azimuthal error

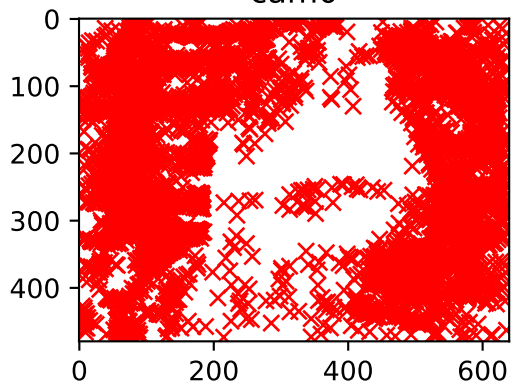cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners