Calibration results
=====================
Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.15522588 -0.16057199 -0.0019773   0.00140648] +- [0.00297721 0.00439325 0.0005621 0.00061624]
projection: [440.80102691 440.28623032 322.42066542 214.52758108] +- [0.35486413 0.35113708 0.87882062 0.70071338]
reprojection error: [-0.000061, 0.000001] +- [0.218999, 0.199025]

cam1 (/cam2/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.14287188 -0.1373778 -0.0014552   0.00135937] +- [0.00280806 0.00416864 0.0005489 0.00078927]
projection: [441.35809658 441.03373288 313.98202708 232.22509731] +- [0.33519185 0.34494681 1.00187199 0.73256401]
reprojection error: [-0.000086, 0.000001] +- [0.211863, 0.204745]

baseline T_1_0:
q: [-0.01182649 -0.00491321 -0.02354644 0.99964072] +- [0.0008175 0.00120866 0.00015816]
t: [0.12427062 0.00155246 -0.0019328] +- [0.00041012 0.00032869 0.00090348]

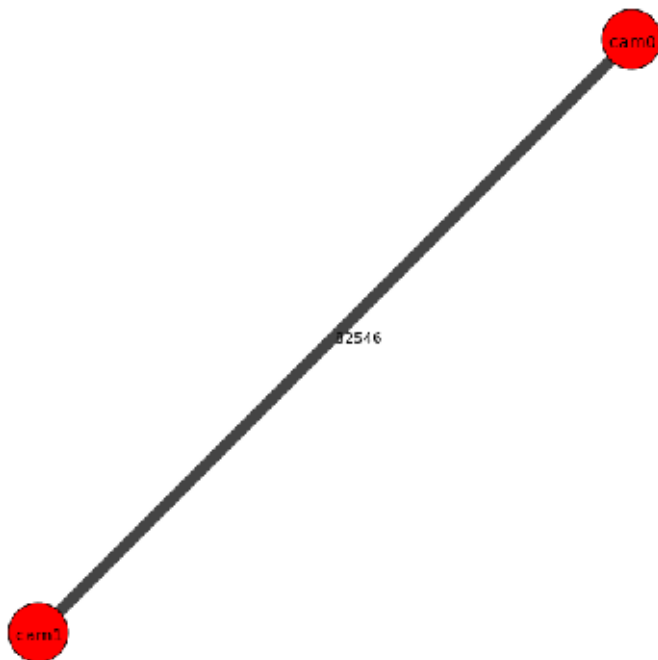Target configuration
=====================
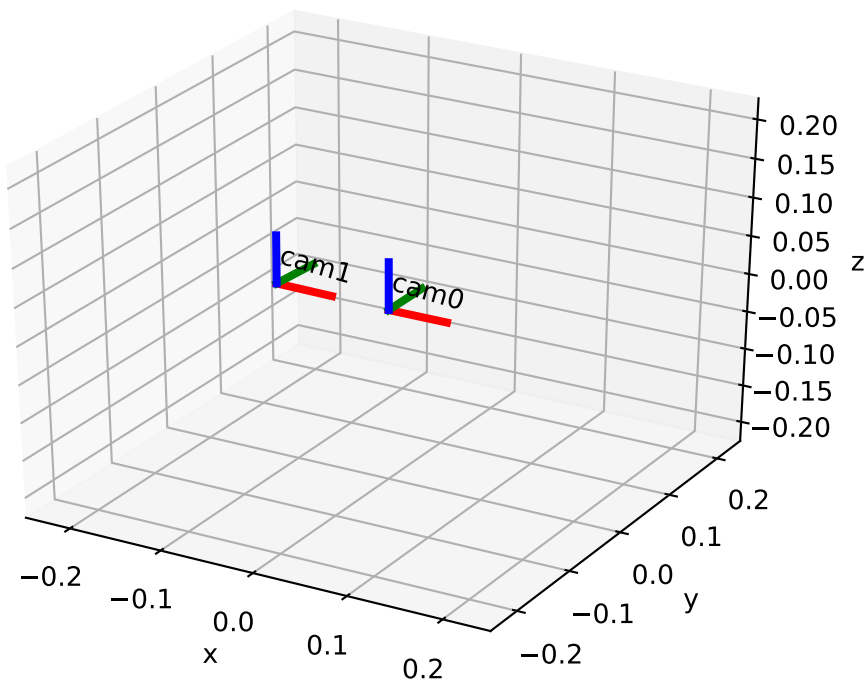
Type: aprilgrid
Tags:
Rows: 6
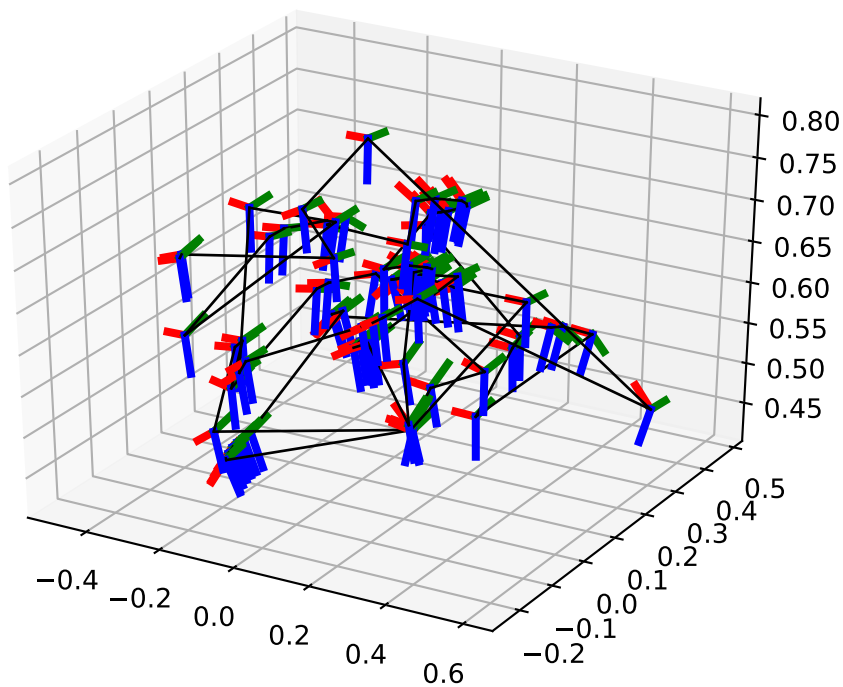Cols: 6
Size: 0.0315 [m]
Spacing 0.009513 [m]

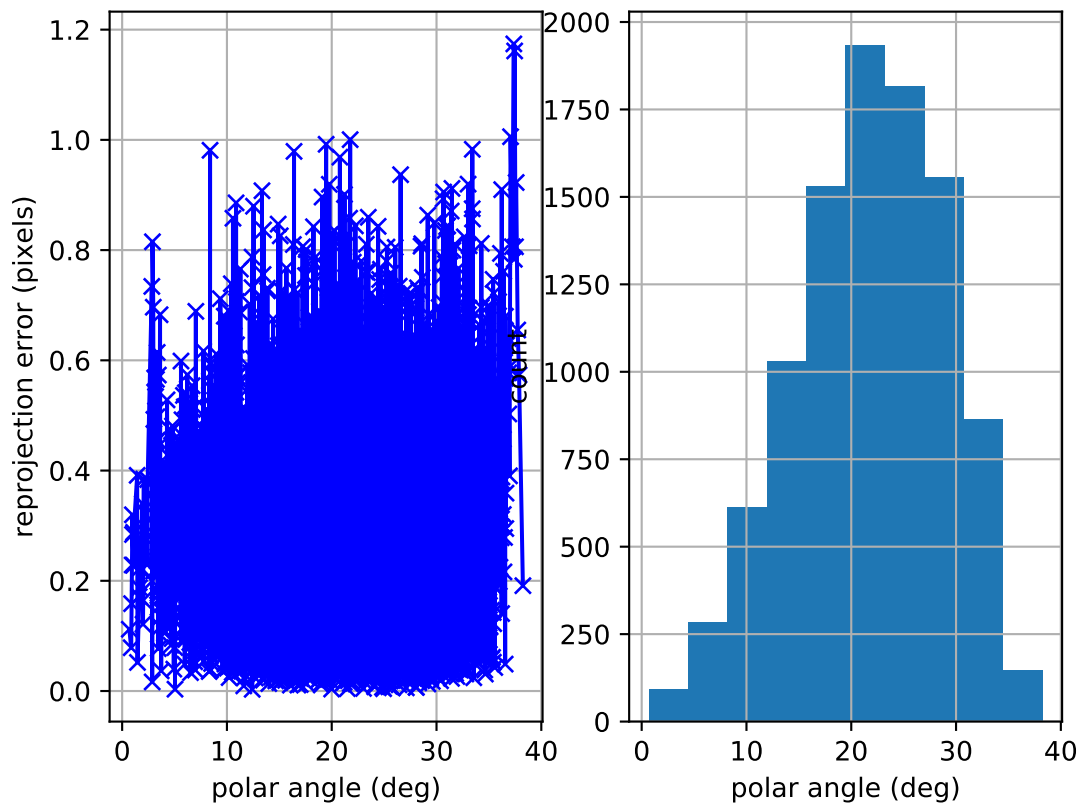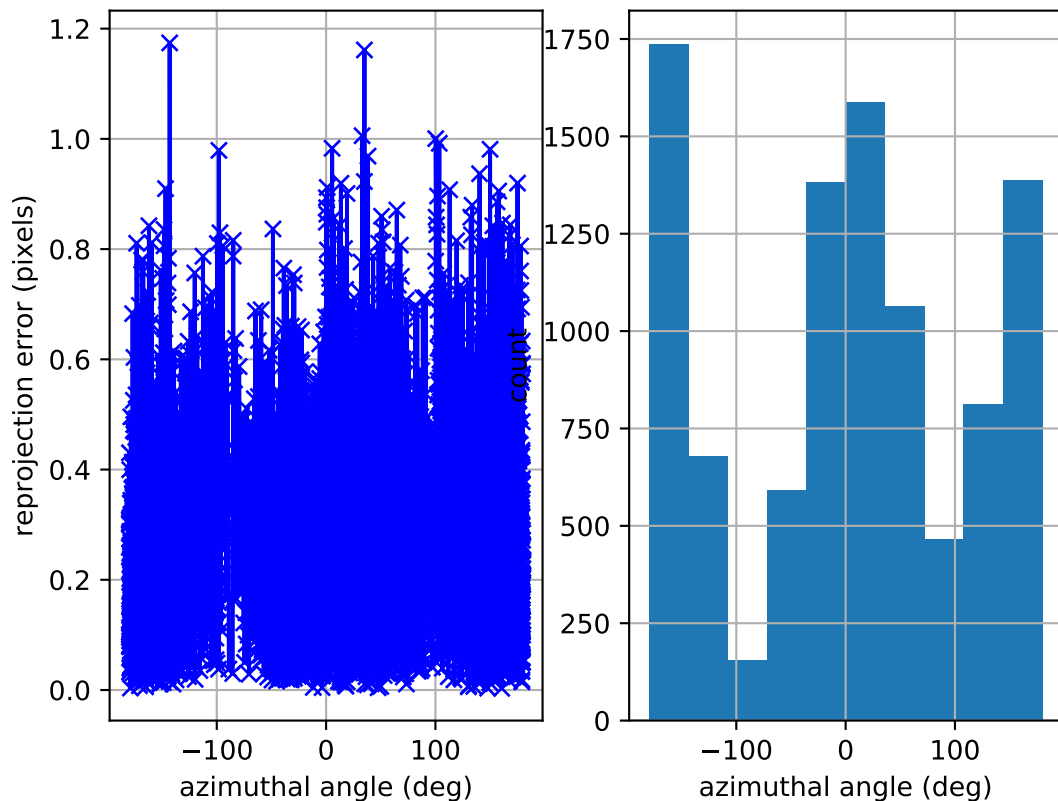Inter-camera observations graph (edge weight=#mutual obs.)
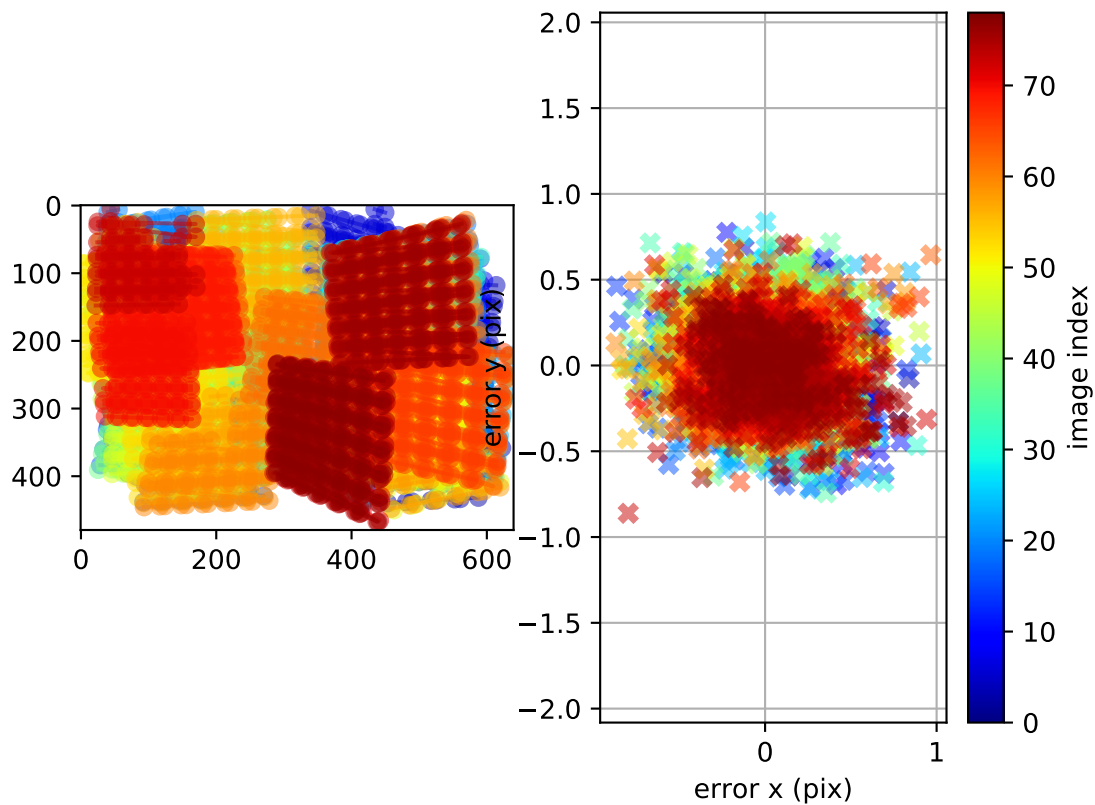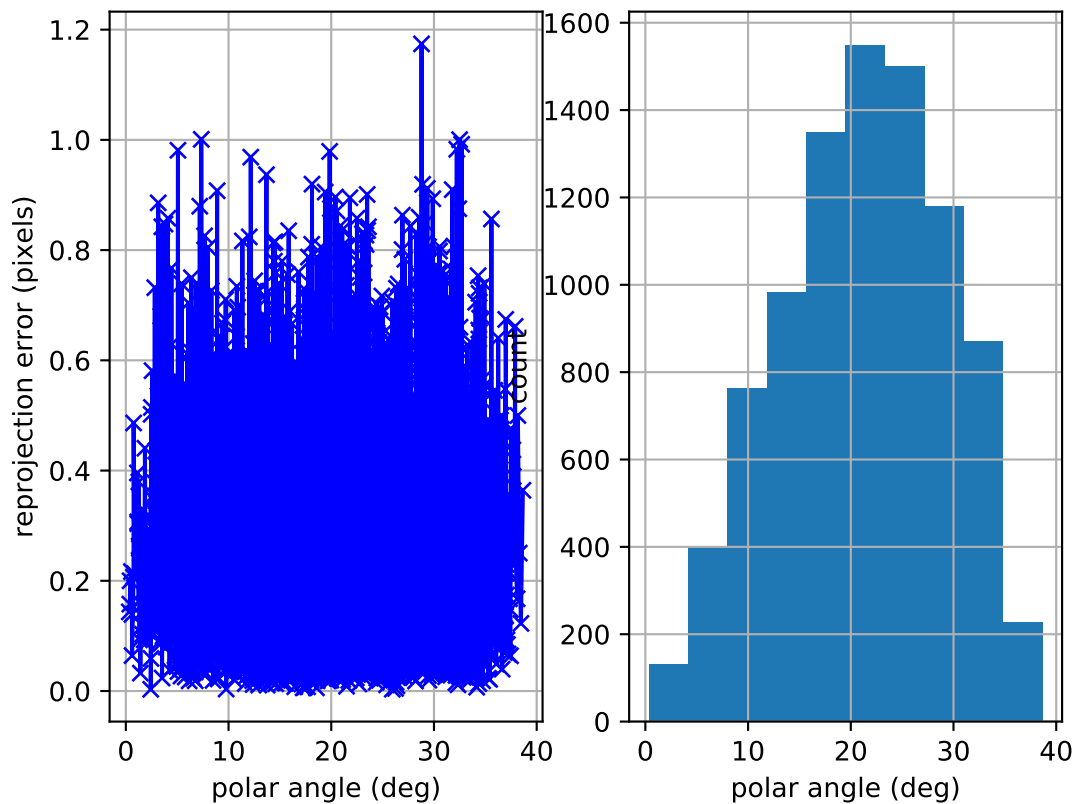
camera system

cam0: estimated poses

cam0: polar error

cam0: azimuthal error
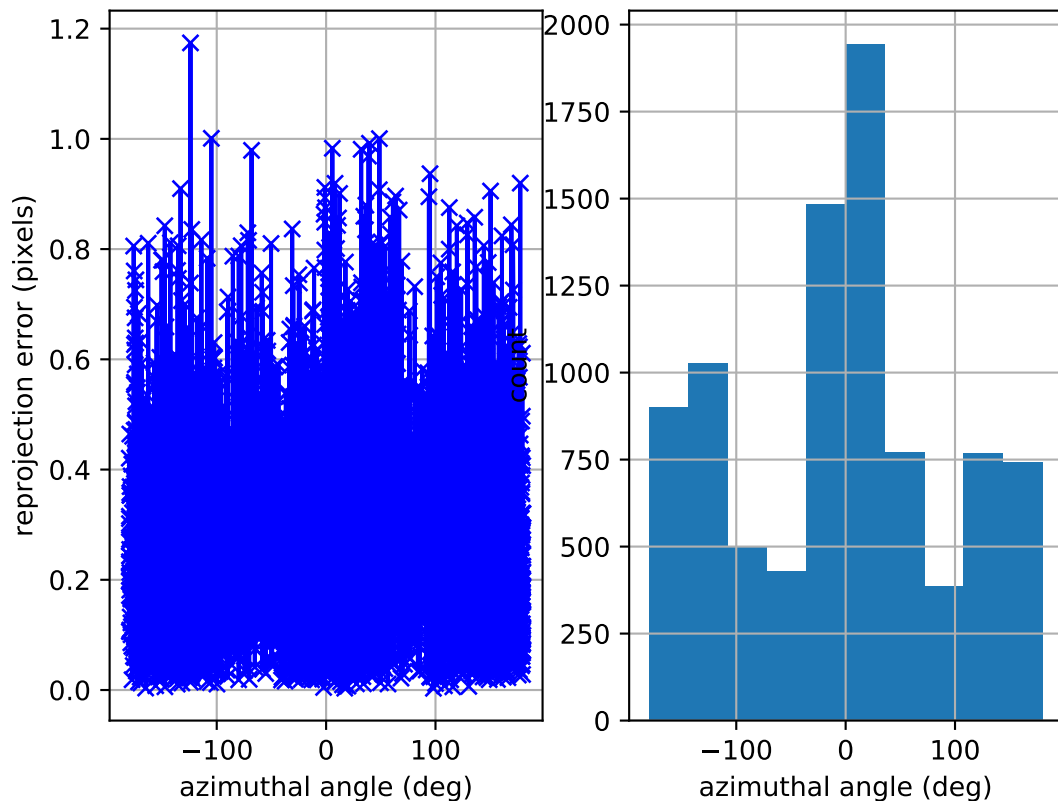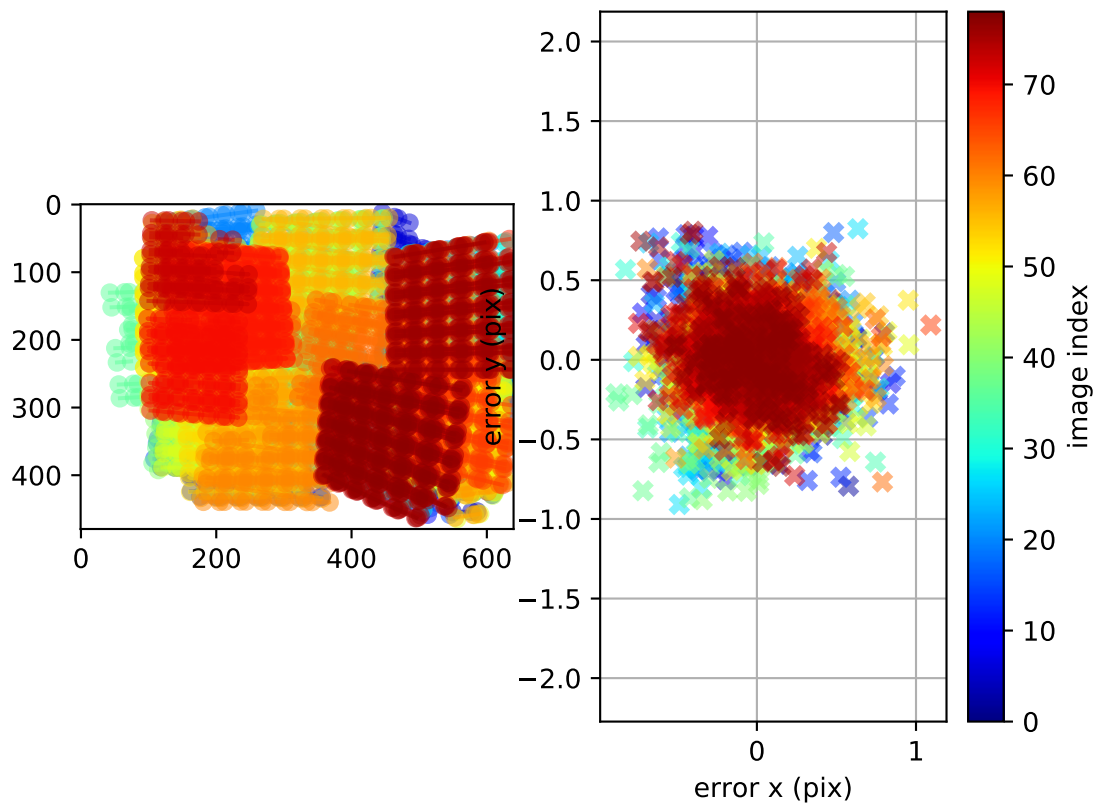
cam0: reprojection errors
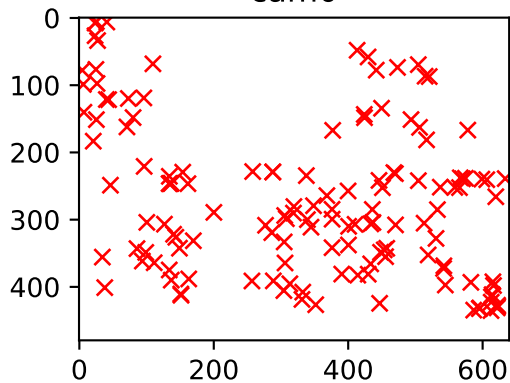
cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners