Calibration results
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Camera-system parameters:
cam0 (/cam0/image_raw):
  type: <class 'aslam_cv.libaslam_cv_python.DistortedOmniCameraGeometry'>
  distortion: [-0.22597517 -1.61331058 0.00004971 0.00103372] +- [0.08815384 0.01037665 0.00328922 0.00436343]
  projection: [2.18627634 2218.56824293 2217.61288206 338.28436028 250.35739663] +- [0.0384041 0.09563418
0.09565815 0.26763683 0.67497756]
  reprojection error: [-0.000015, 0.000002] +- [0.194403, 0.189541]

cam1 (/cam2/image_raw):
  type: <class 'aslam_cv.libaslam_cv_python.DistortedOmniCameraGeometry'>
  distortion: [-0.44128533 0.23729951 0.00102212 -0.00218587] +- [0.01916303 0.10019503 0.00132764 0.00138025]
  projection: [0.25006679 838.0461279   837.87365135 319.35105275 237.86936087] +- [0.01518181 0.1506326
0.15065638 0.2508855 0.65256972]
  reprojection error: [0.000007, -0.000005] +- [0.156674, 0.157491]

baseline T_1_0:
  q: [-0.00017988 -0.00347628 0.00099811 0.99999344] +- [0.00200071 0.00083363 0.0002297]
  t: [0.10313087 -0.0005939   0.00130075] +- [0.00019153 0.00017089 0.00114176]

Target configuration
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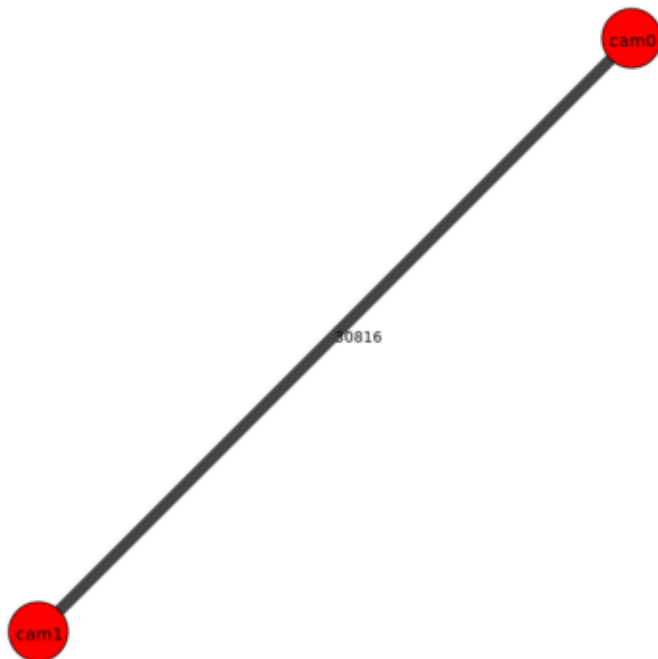
 Type: checkerboard
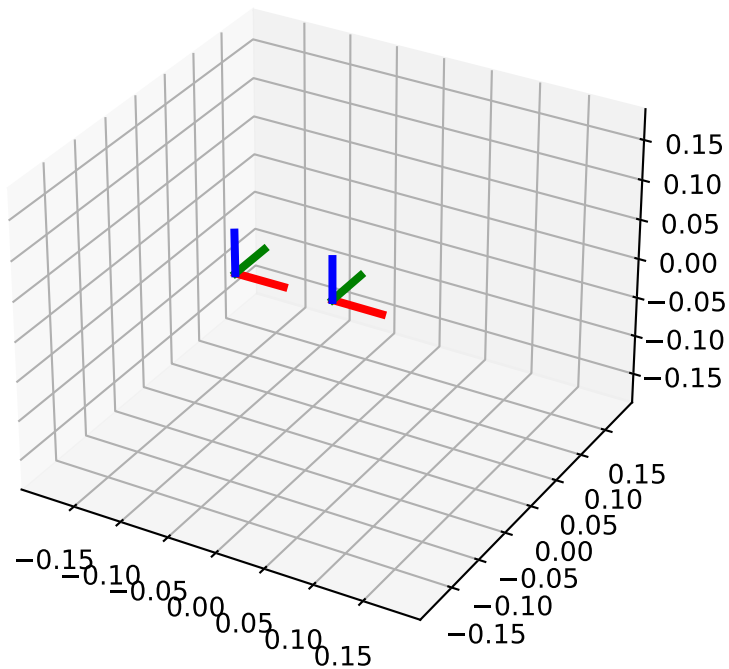 Rows
  Count: 8
  Distance: 0.026 [m]
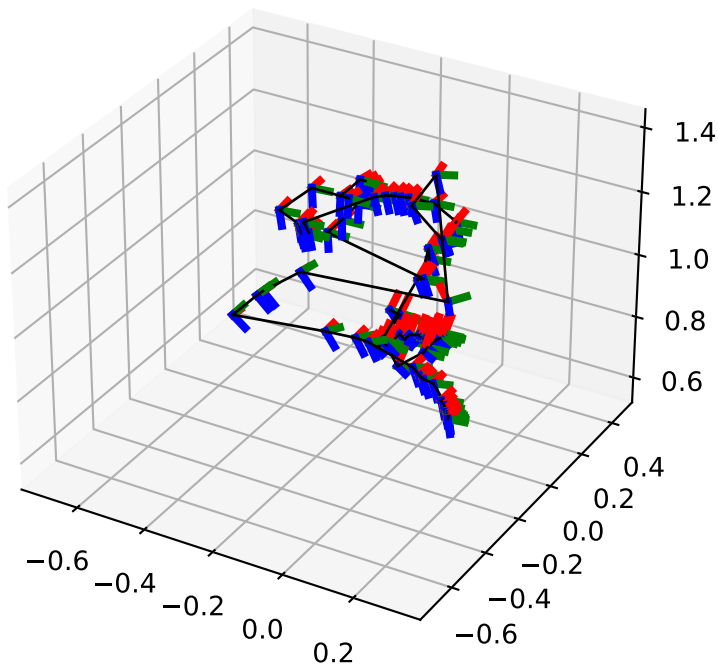 Cols
  Count: 6
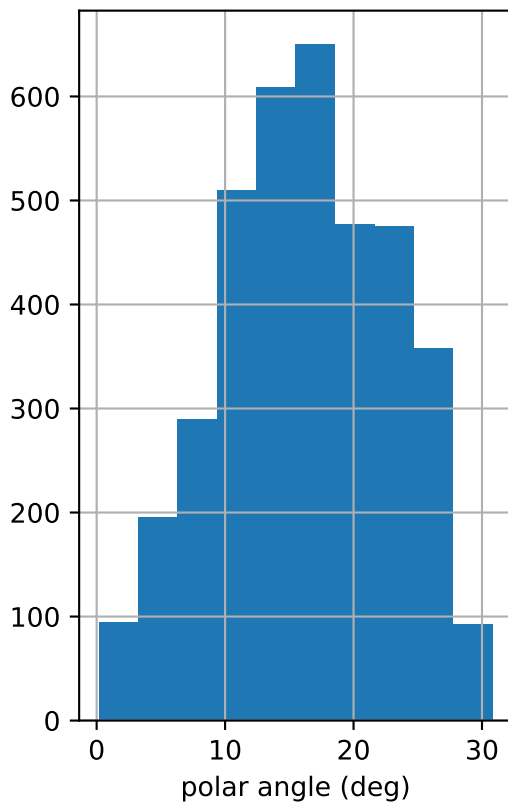 Distance: 0.026 [m]

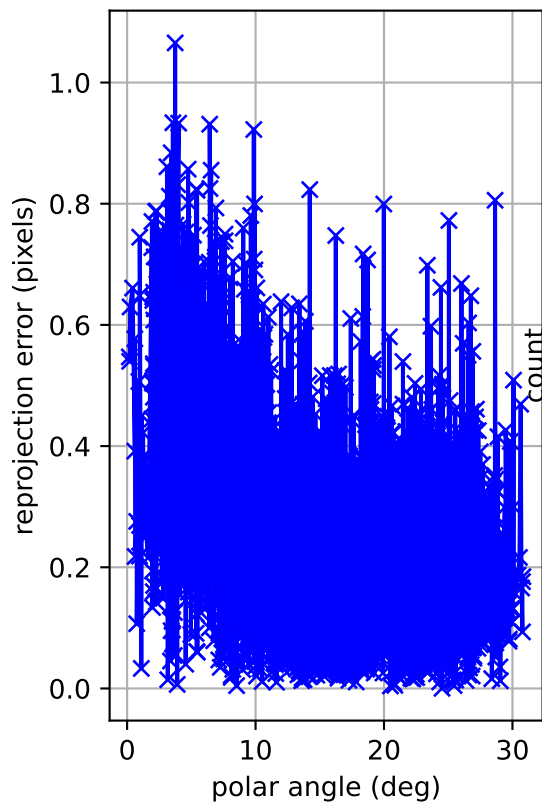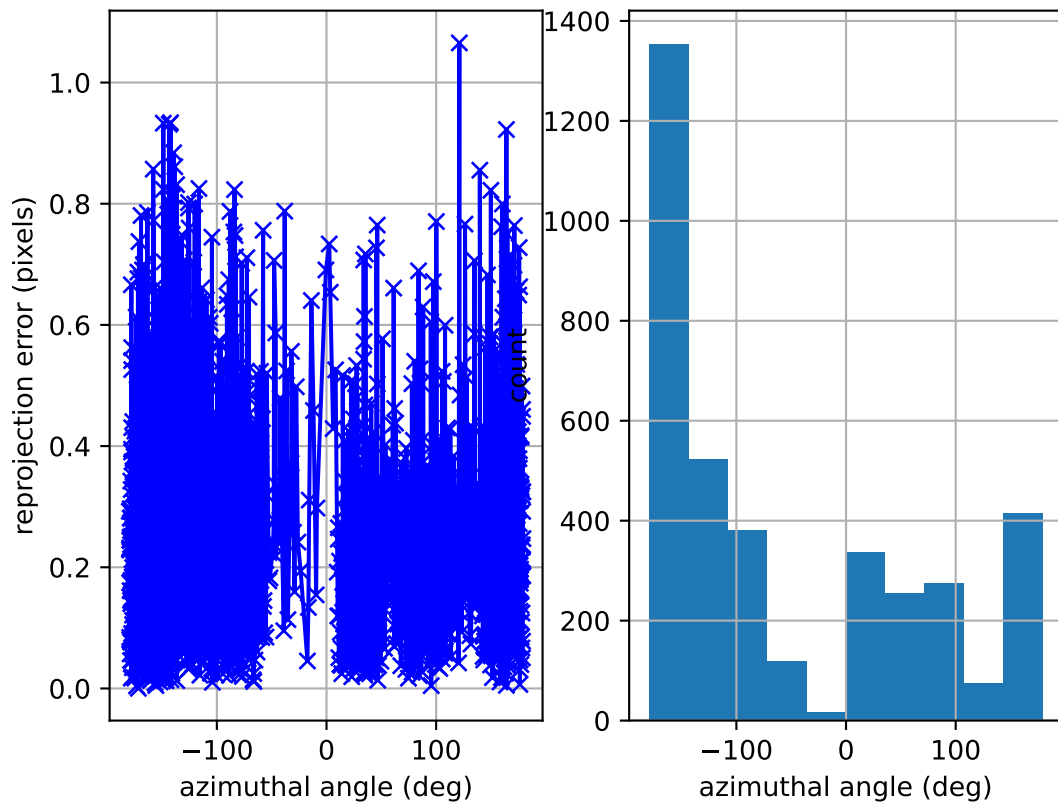Inter-camera observations graph (edge weight=#mutual obs.)
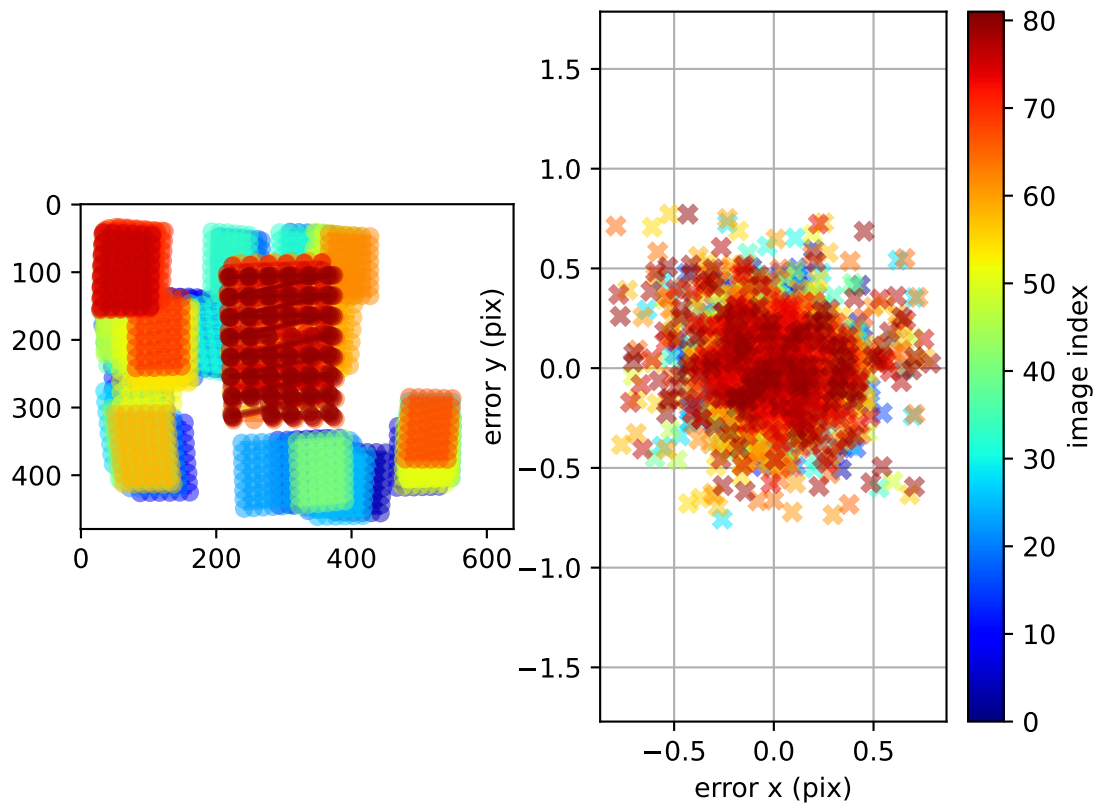
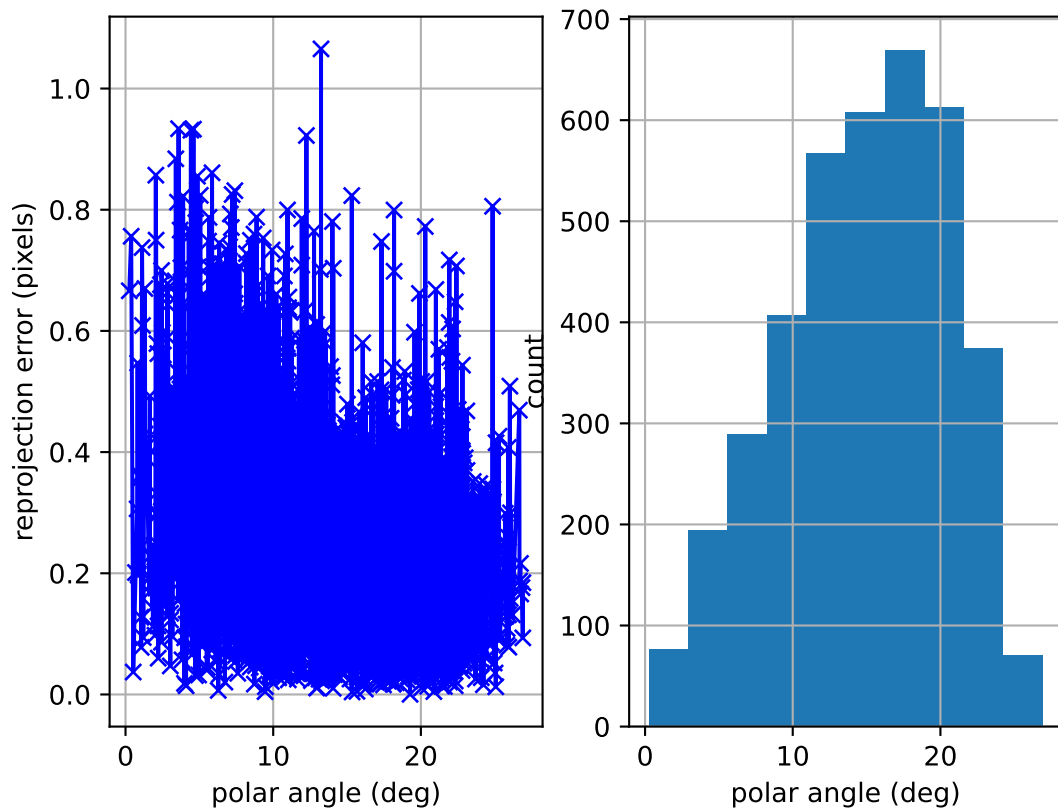camera system

cam0: estimated poses

cam0: polar error

cam0: azimuthal error
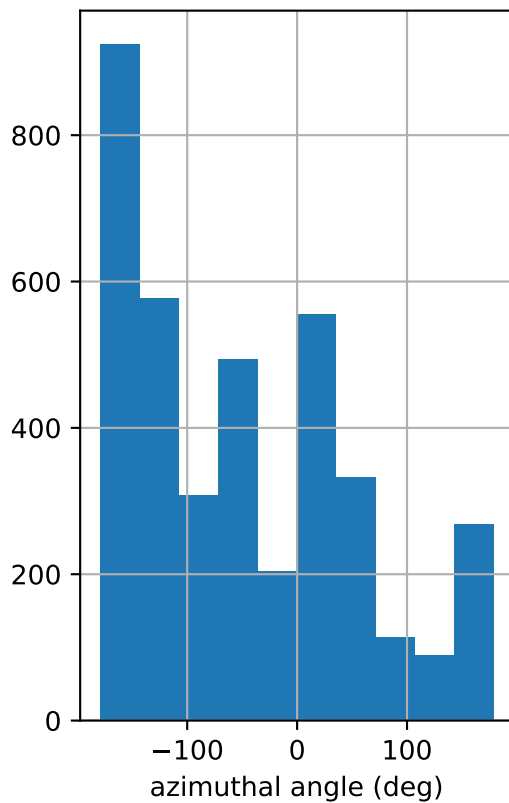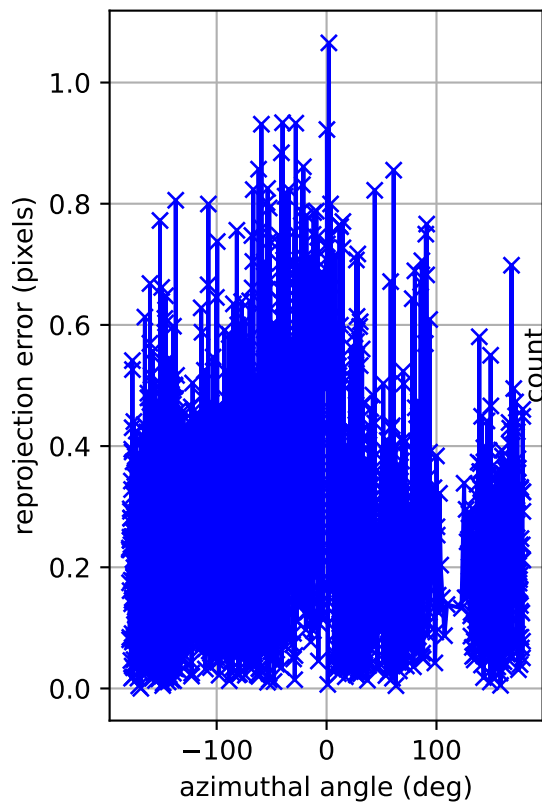
cam0: reprojection errors

cam1: polar error

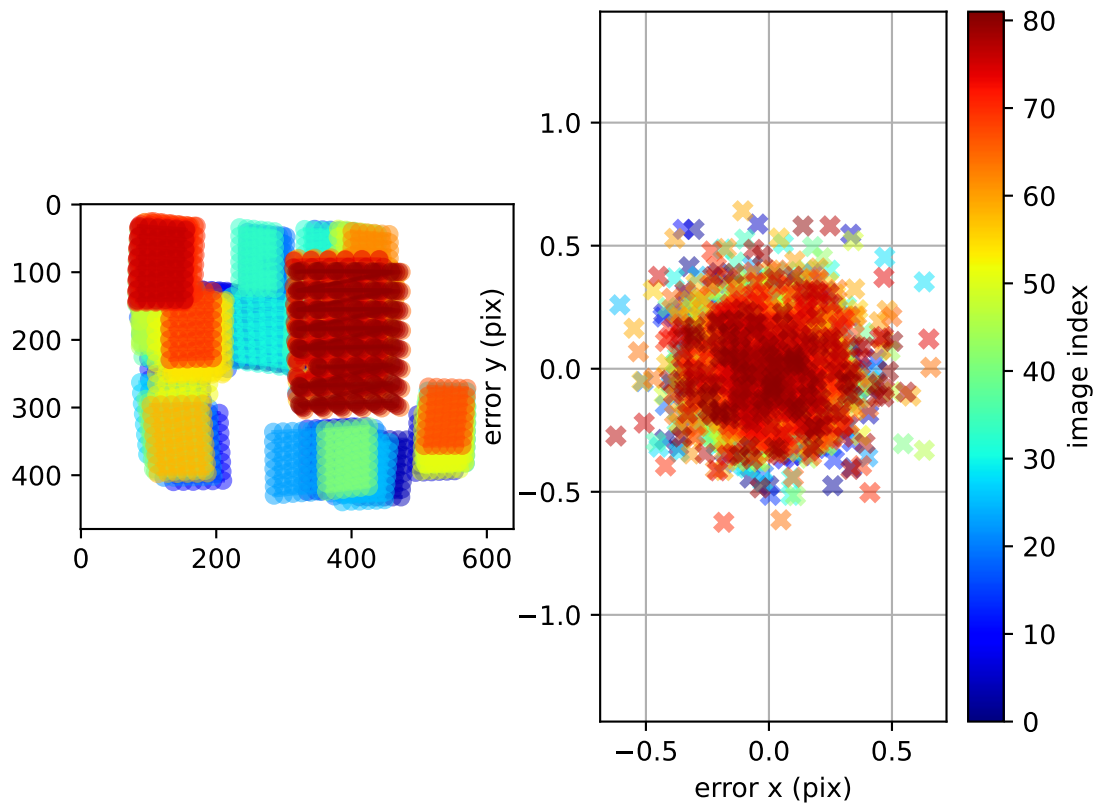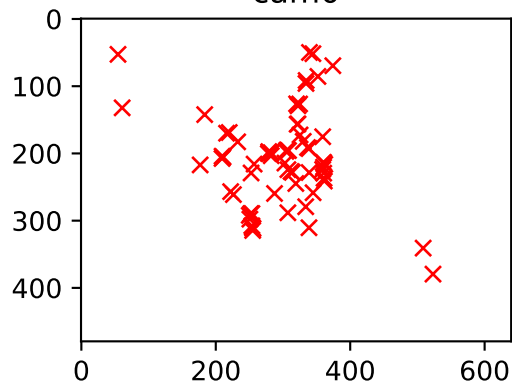cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners