Calibration results
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Camera-system parameters:
cam0 (/b1/b1_side_right_cam/infra1/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00408286 -0.00349172 -0.00002717 0.00215719] +- [0.00115761 0.00147464 0.00023307 0.00026626]
projection: [389.31042886 389.92976827 323.19849317 237.69039429] +- [0.3409004 0.34054246 0.34826005 0.30302305]
reprojection error: [0.000008, -0.000000] +- [0.129186, 0.098671]

cam1 (/b1/b1_side_right_cam/infra2/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00247969 -0.00213493 0.00010479 0.00216571] +- [0.00115117 0.0012046 0.0002295 0.00028524]
projection: [389.76365652 390.21679031 323.16071121 238.24265438] +- [0.34736492 0.34899134 0.3689486 0.31115402]
reprojection error: [-0.000008, -0.000000] +- [0.131832, 0.099300]

baseline T_1_0:
q: [-0.00079851 0.0004487   0.00010223 0.99999958] +- [0.00062479 0.0008361 0.00010438]
t: [-0.0502337 -0.00003823 -0.00019158] +- [0.00003198 0.0000272 0.00007839]

Target configuration
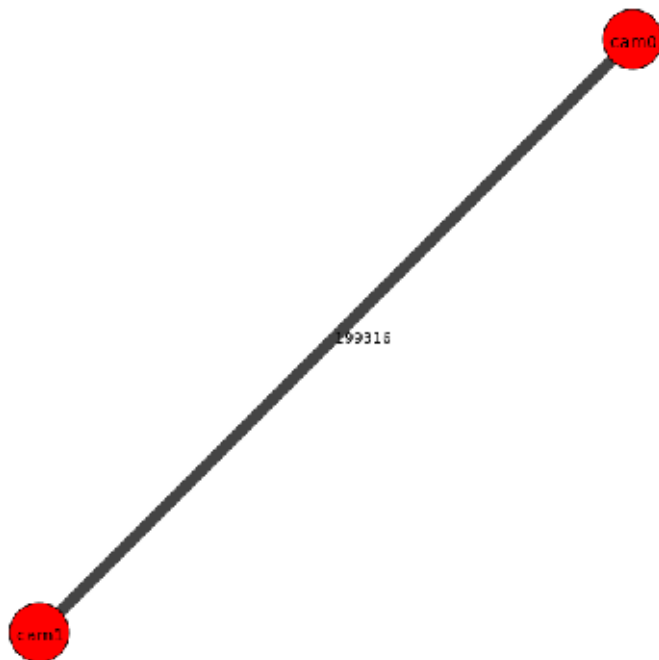====================

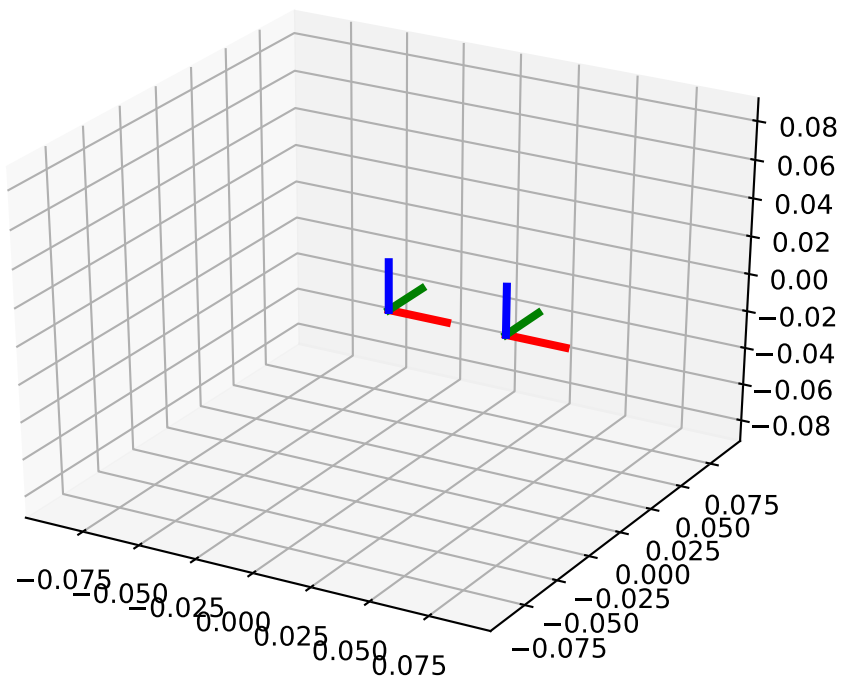Type: aprilgrid
Tags:
Rows: 6
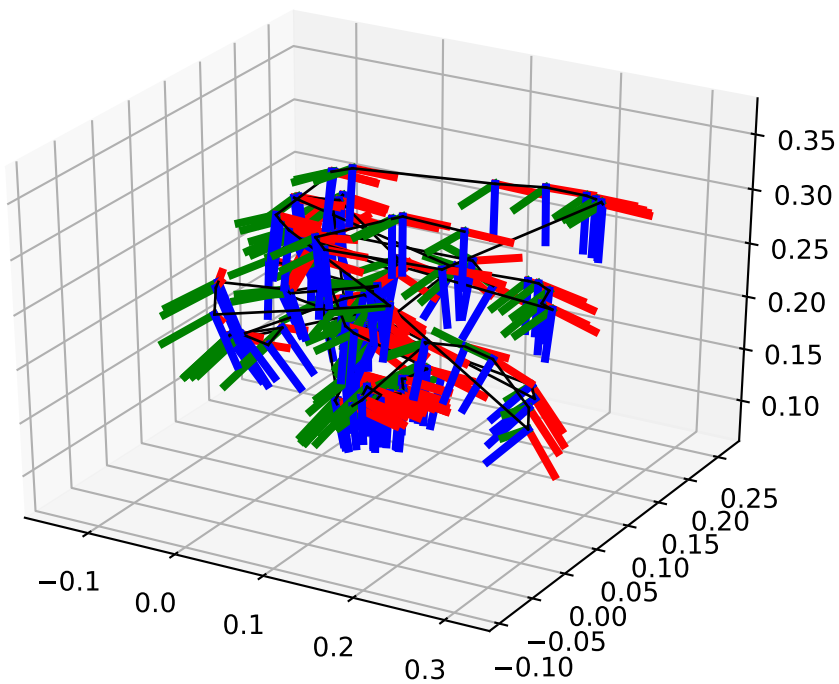Cols: 6
Size: 0.02 [m]
Spacing 0.006 [m]

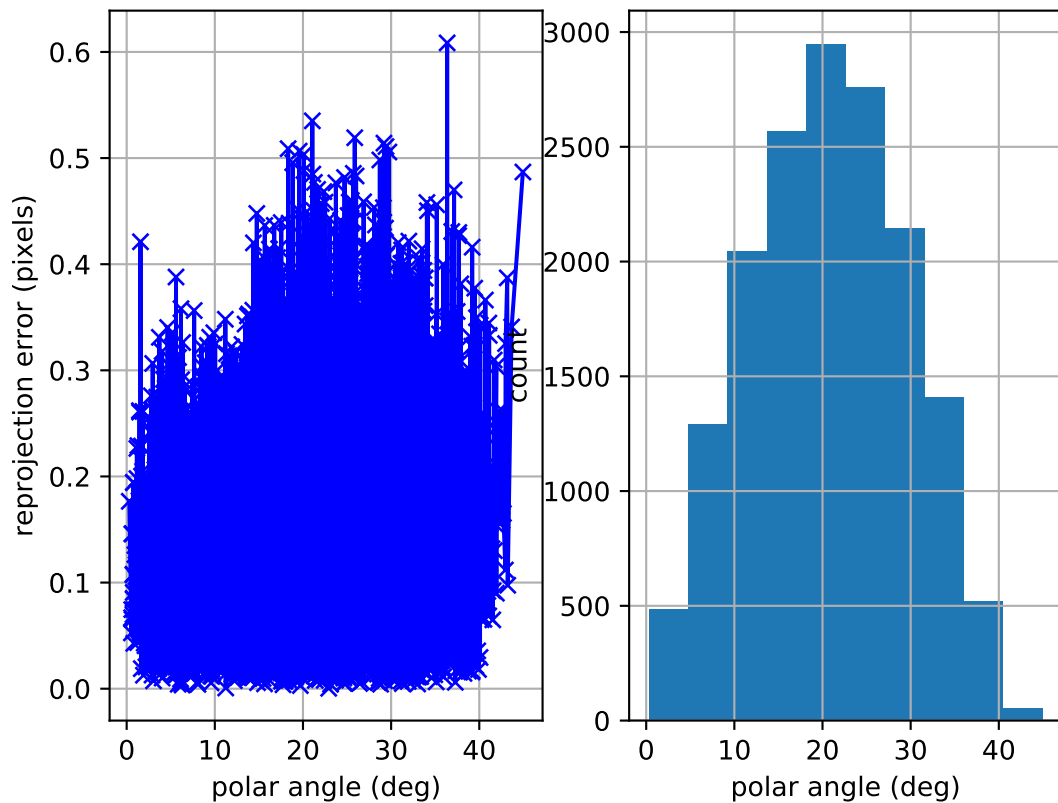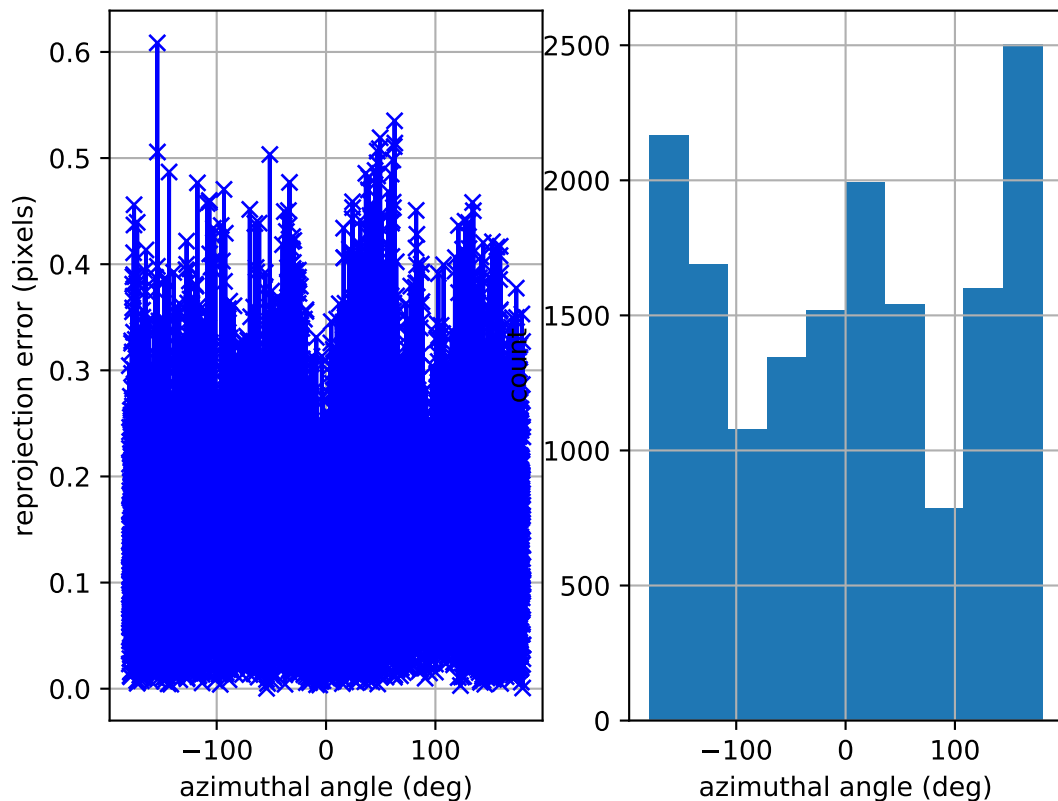Inter-camera observations graph (edge weight=#mutual obs.)
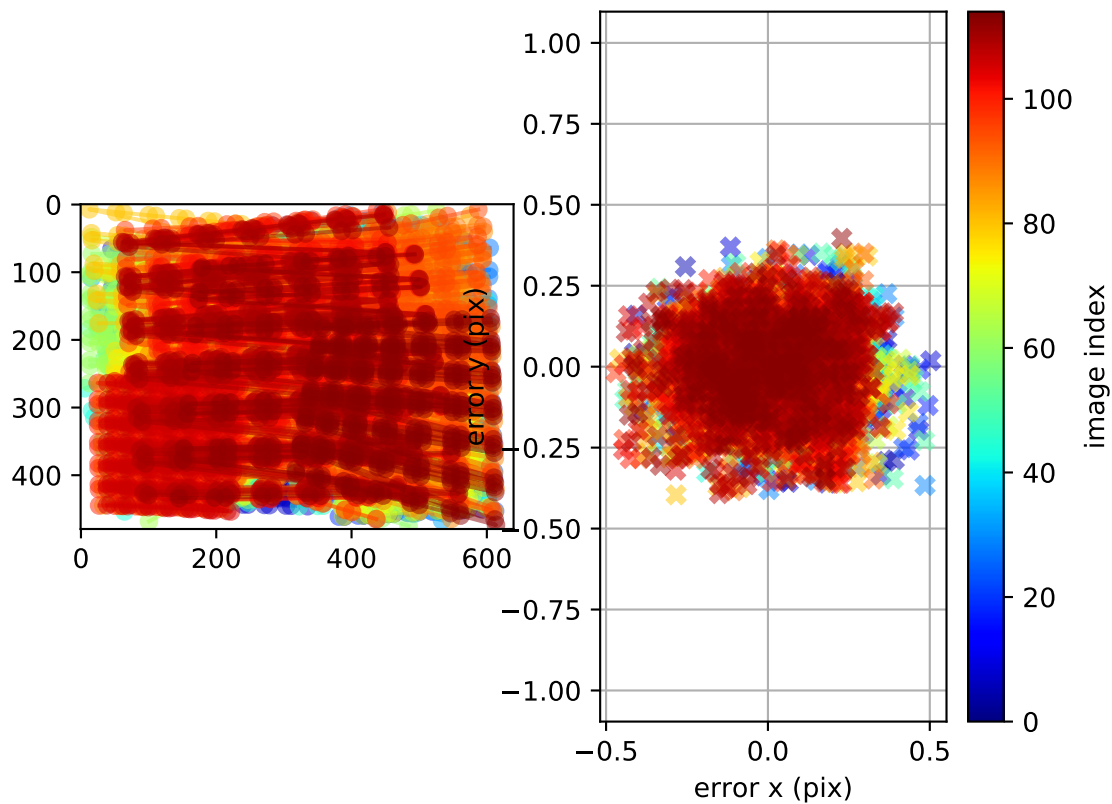
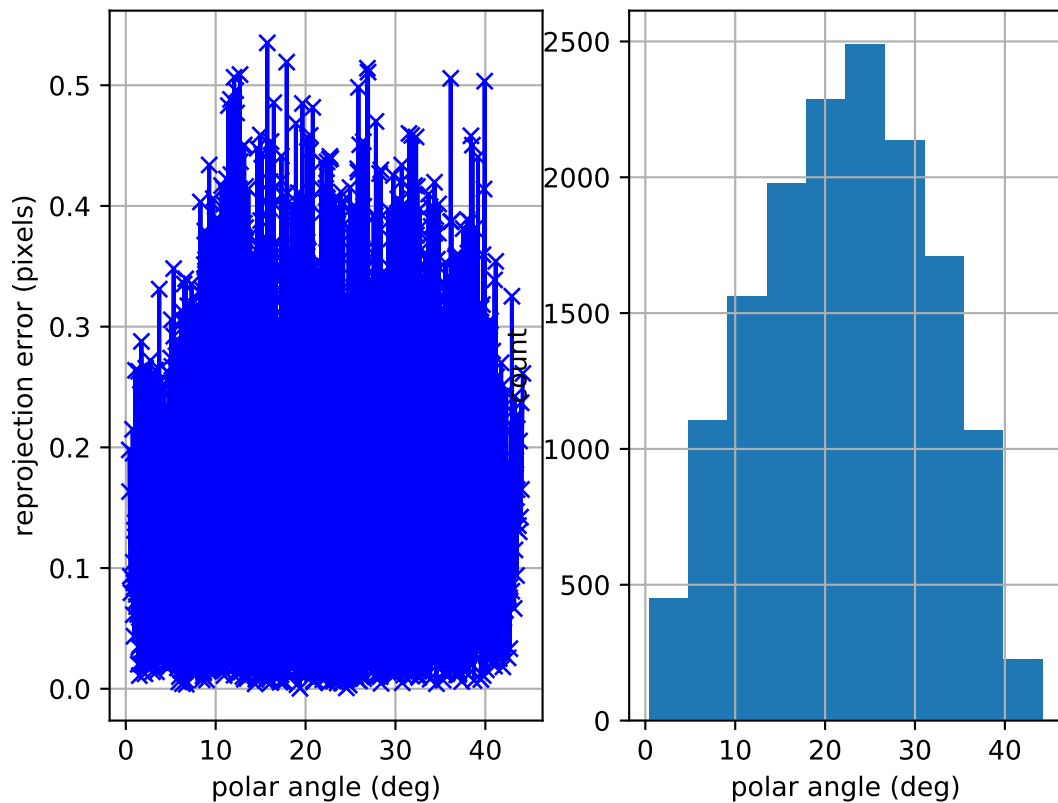camera system

cam0: estimated poses
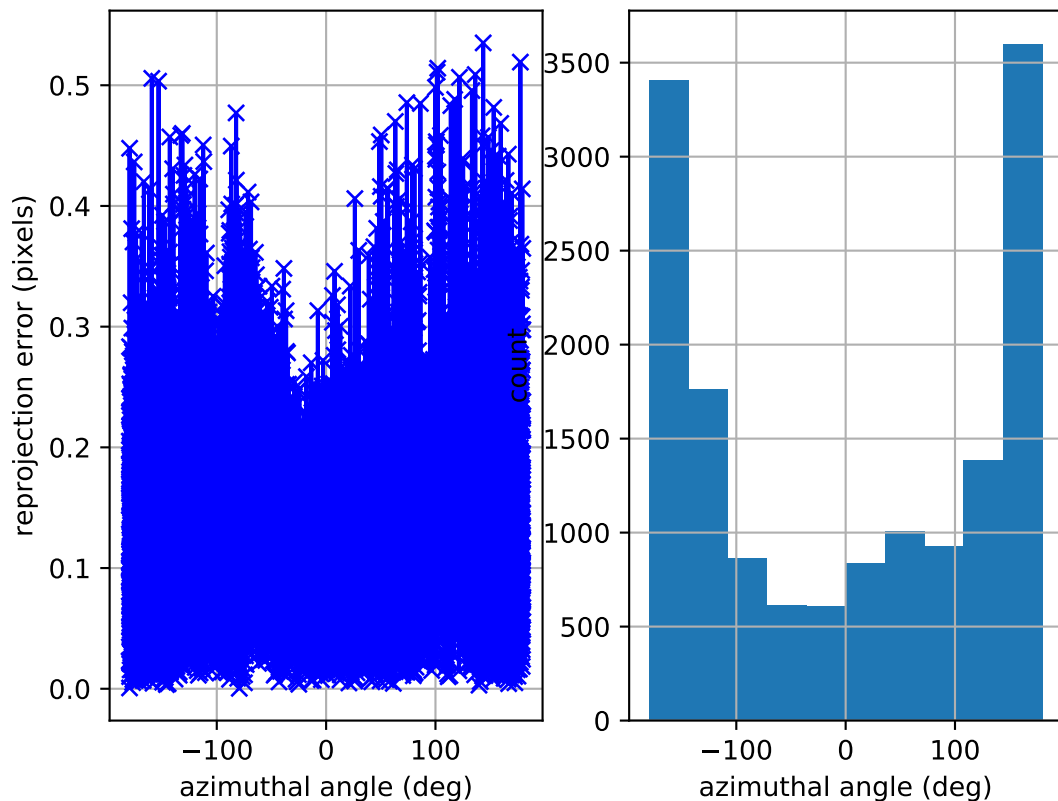
cam0: polar error

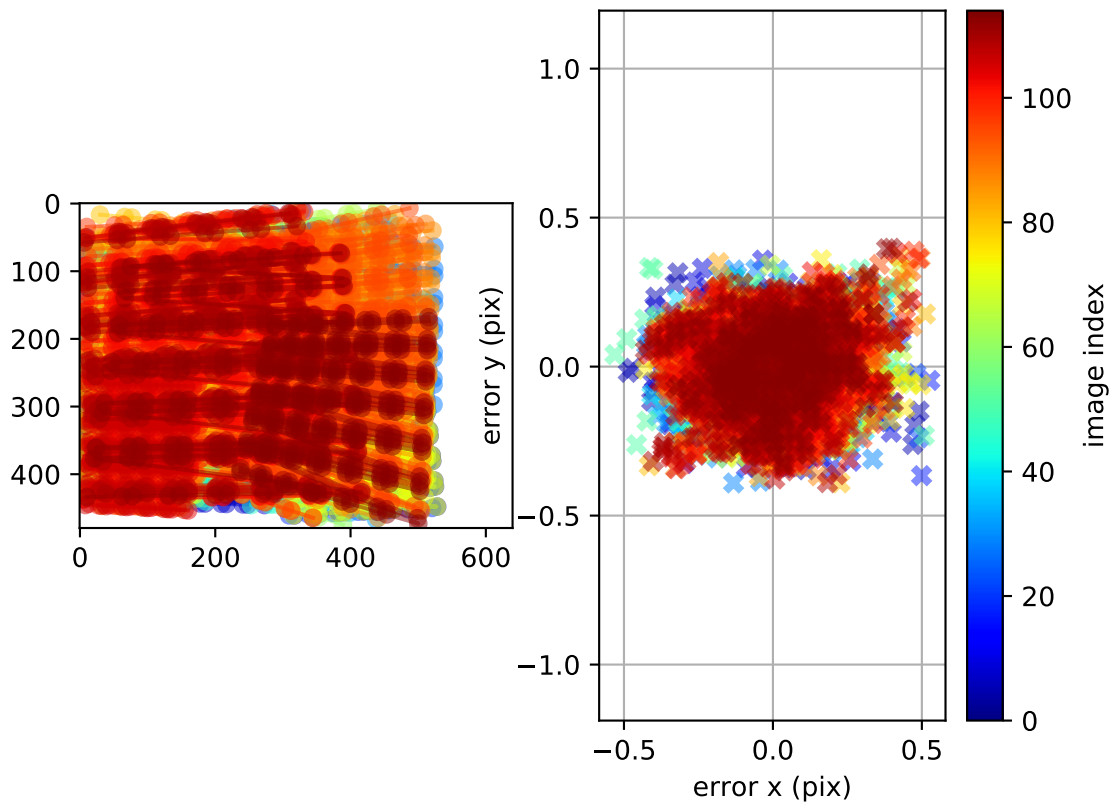cam0: azimuthal error

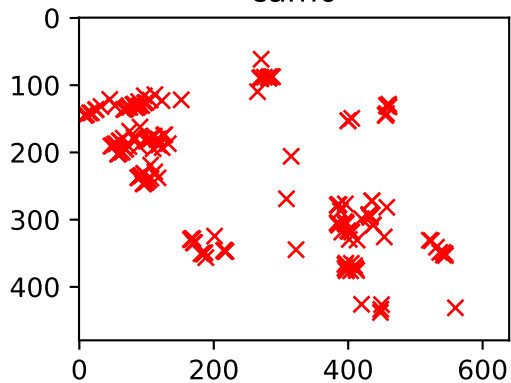cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners