Calibration results
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Camera-system parameters:
cam0 (/b1/b1_side_left_cam/infra1/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00302107 -0.00421186 0.00055245 -0.00065413] +- [0.00116313 0.00152698 0.00021492 0.00024178]
projection: [392.42745309 392.86236028 322.20548988 232.38136198] +- [0.32471932 0.32136427 0.29528598
0.27756343]
reprojection error: [-0.000013, -0.000003] +- [0.155530, 0.110807]

cam1 (/b1/b1_side_left_cam/infra2/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [-0.00041008 0.00013058 0.00060018 -0.00069001] +- [0.00113587 0.00126388 0.0002192 0.00026261]
projection: [392.29125531 392.8814131 323.11551822 232.26433393] +- [0.32341592 0.32388079 0.31291612
0.28687908]
reprojection error: [0.000011, 0.000001] +- [0.143793, 0.102525]

baseline T_1_0:
q: [0.00325495 0.00172736 -0.00011914 0.9999932] +- [0.00061662 0.00079922 0.00009736]
t: [-0.05008352 0.00004541 -0.00015976] +- [0.00002239 0.00001998 0.00005746]

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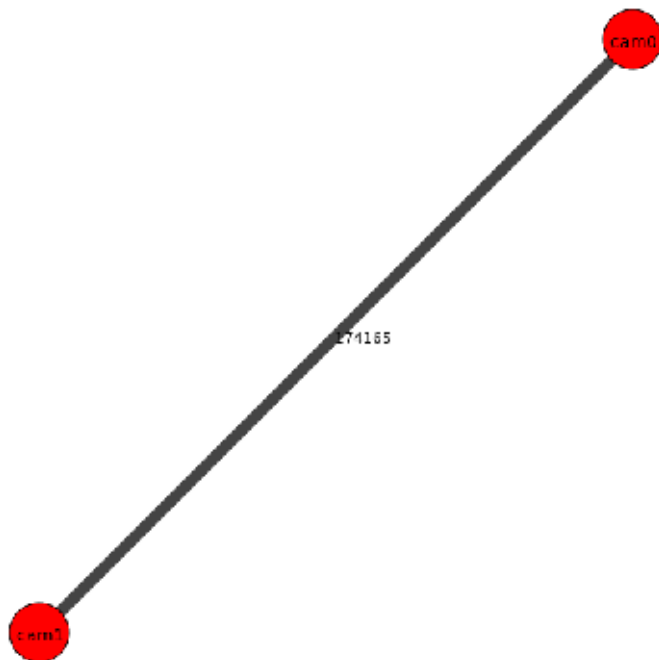====================

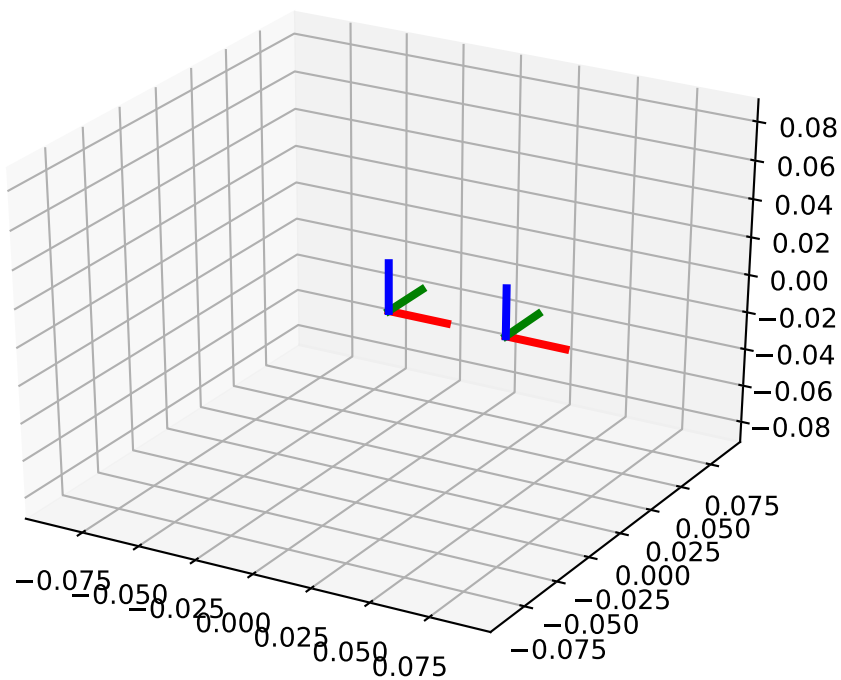Type: aprilgrid
Tags:
Rows: 6
Cols: 6
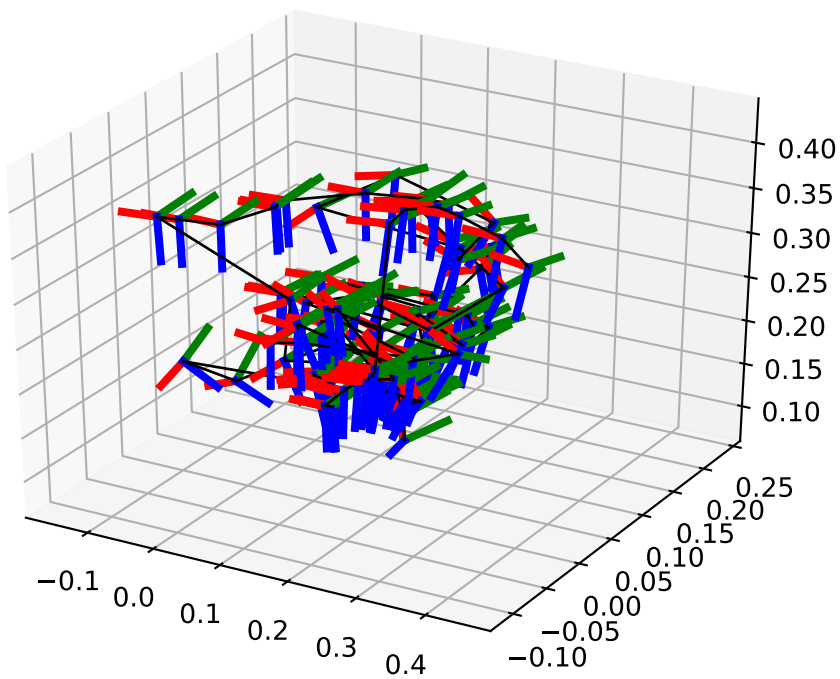Size: 0.02 [m]
Spacing 0.006 [m]

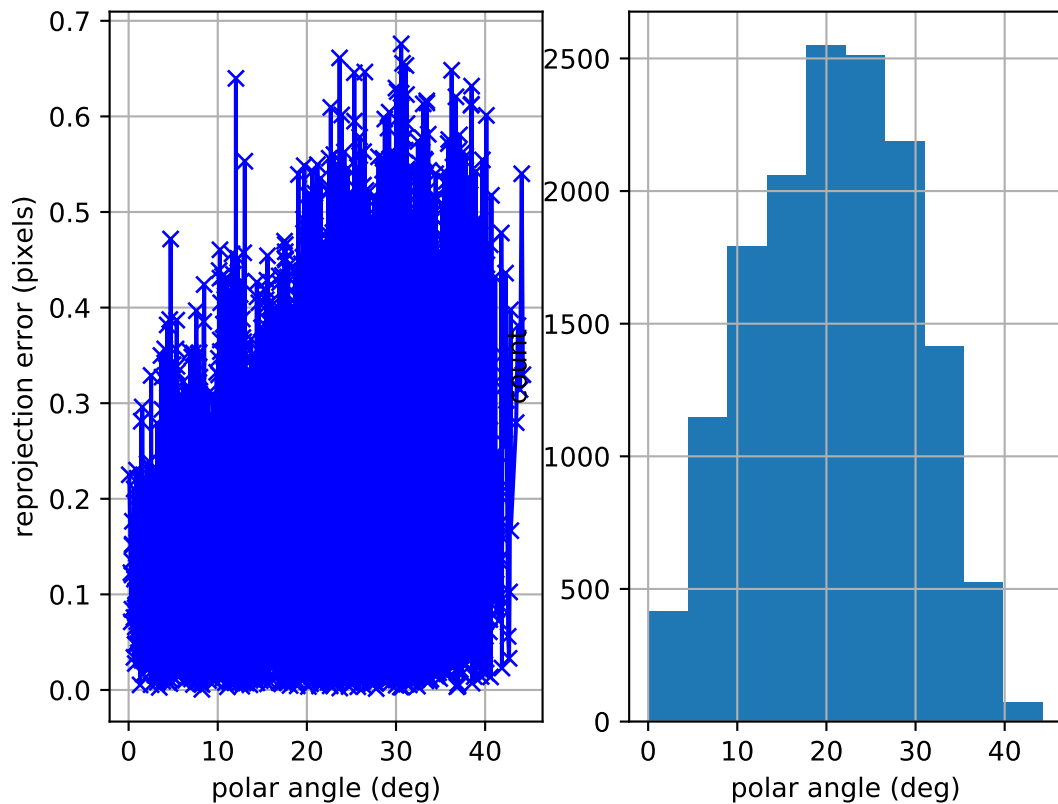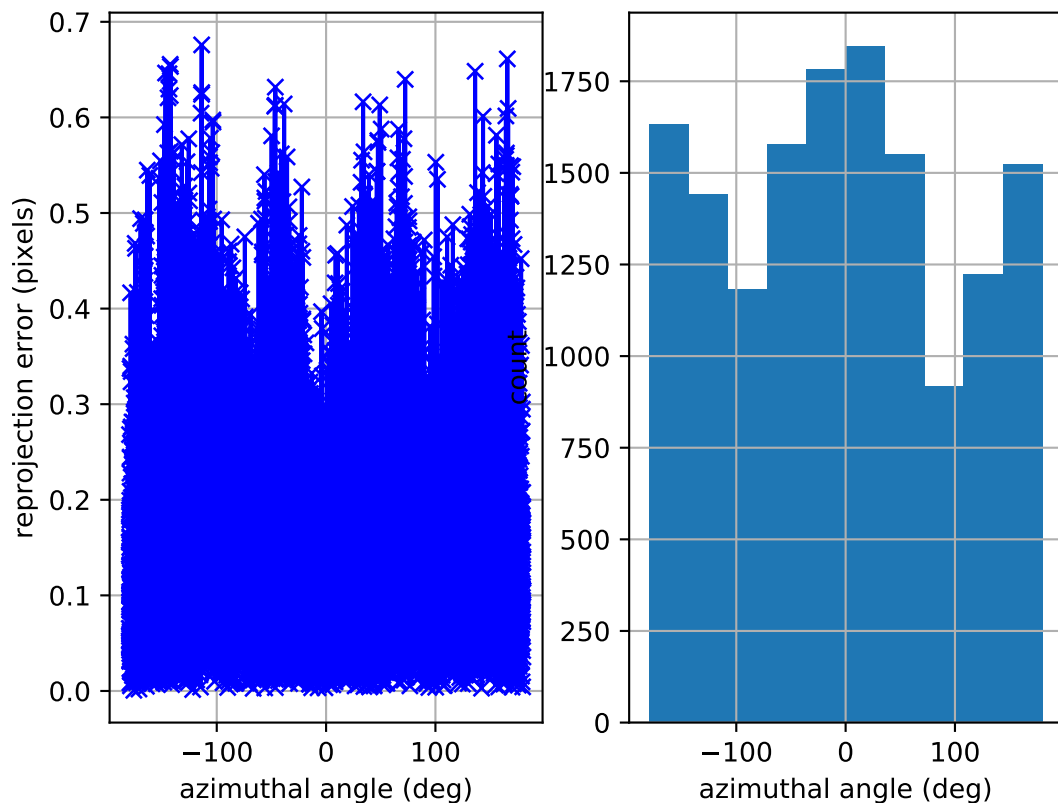Inter-camera observations graph (edge weight=#mutual obs.)
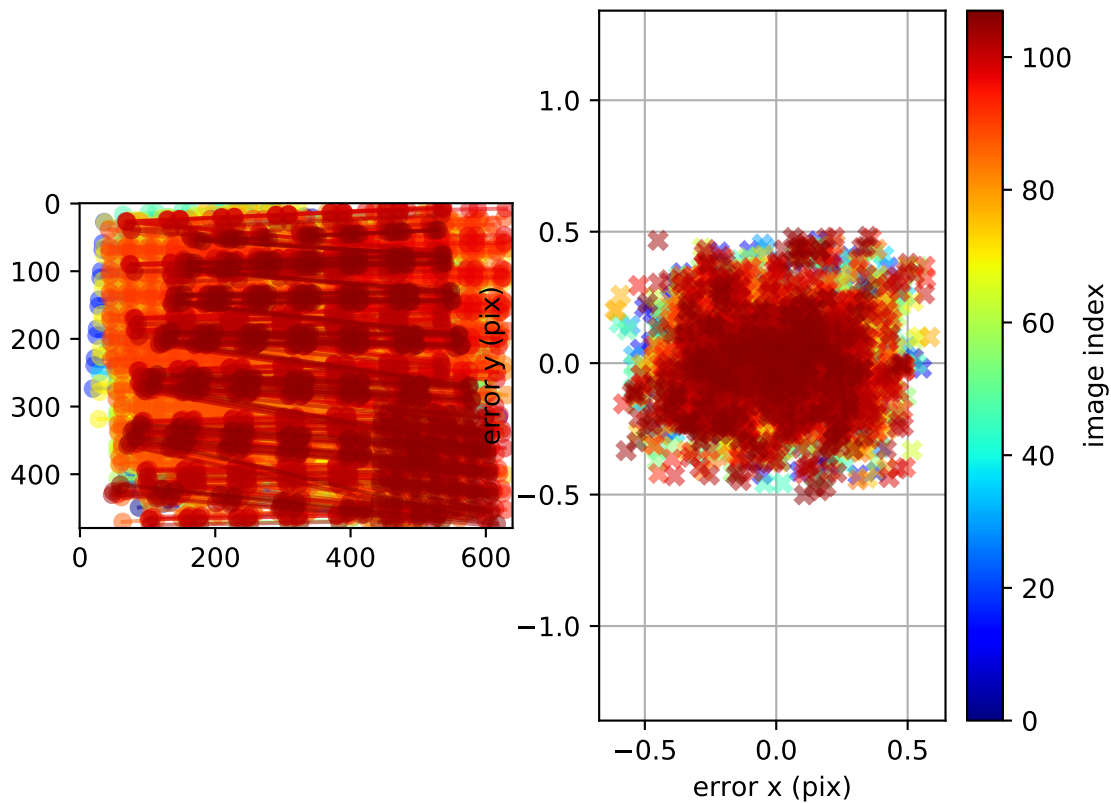
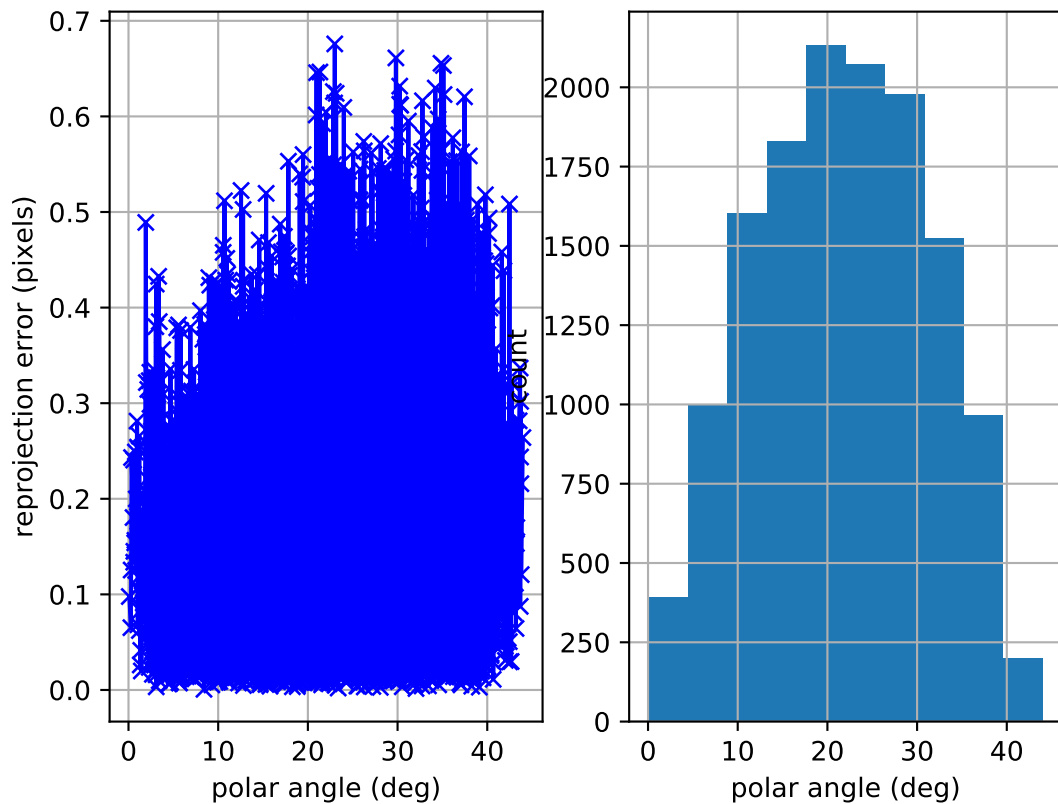camera system

cam0: estimated poses
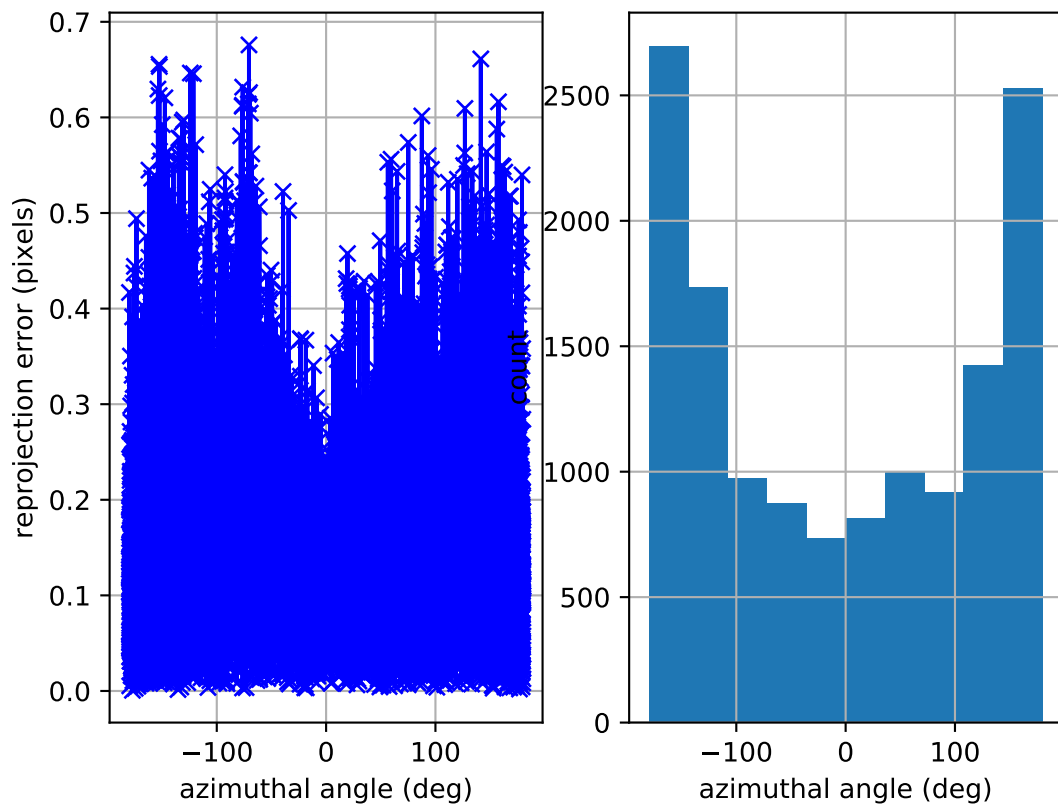
cam0: polar error

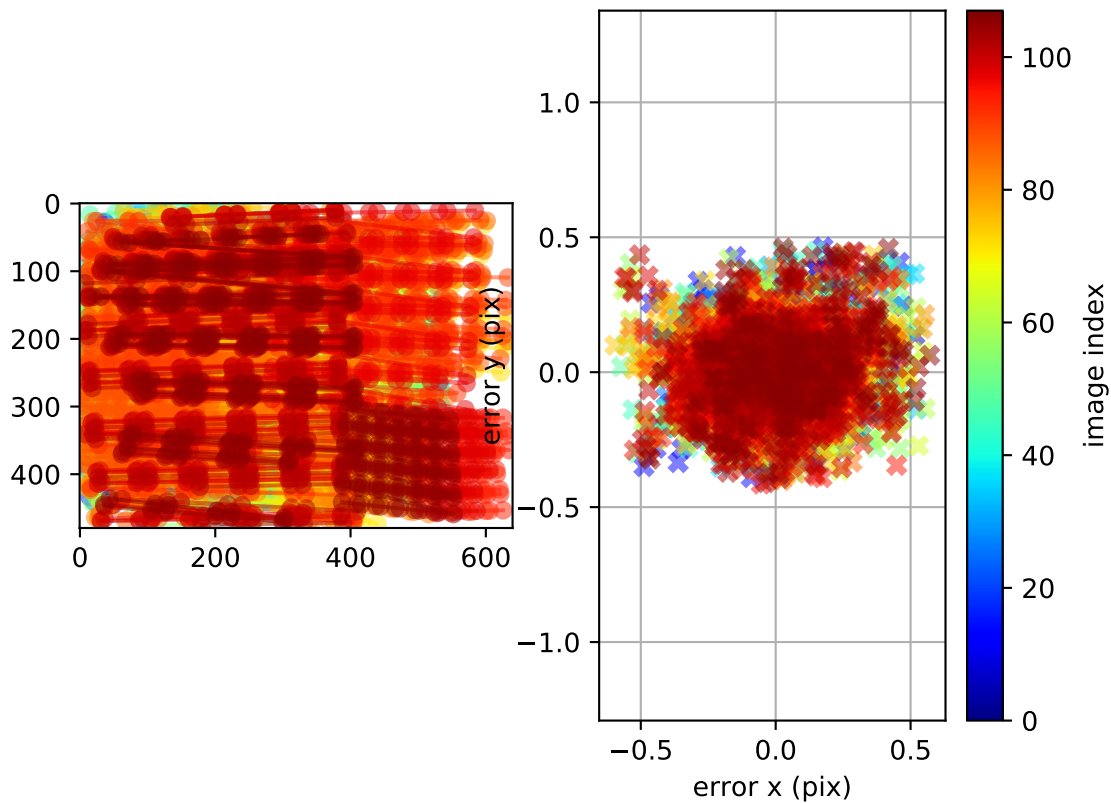cam0: azimuthal error

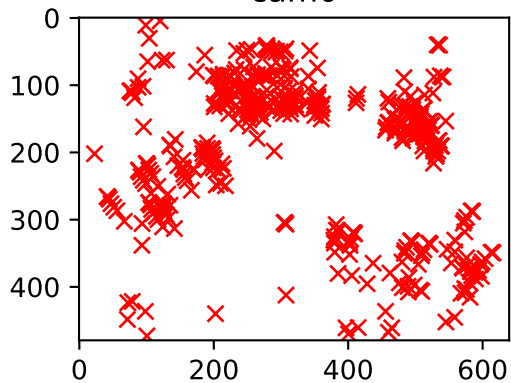cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners