Calibration results
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Camera-system parameters:
cam0 (/camera/infra1/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00184334 -0.00374562 -0.00014742 0.00077265] +- [0.00234914 0.00314636 0.00042128 0.00051297]
projection: [378.33321539 378.64122344 320.94971183 240.13180641] +- [0.16470085 0.17363848 0.65054254 0.6058144]
reprojection error: [0.000008, 0.000001] +- [0.041839, 0.036083]

cam1 (/camera/infra2/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [0.00135004 -0.00371457 -0.0002243   0.00057871] +- [0.00235752 0.0031696 0.00041161 0.00052625]
projection: [378.37076312 378.66253759 320.57176144 240.24808237] +- [0.17759836 0.17692083 0.66702501 0.60356454]
reprojection error: [-0.000001, 0.000001] +- [0.039729, 0.035920]

baseline T_1_0:
q: [-0.00016402 -0.00026174 0.00000989 0.99999995] +- [0.0008654 0.00145619 0.00012124]
t: [-0.04998406 0.000048   -0.0001933] +- [0.00008599 0.00008085 0.00029008]

Target configuration
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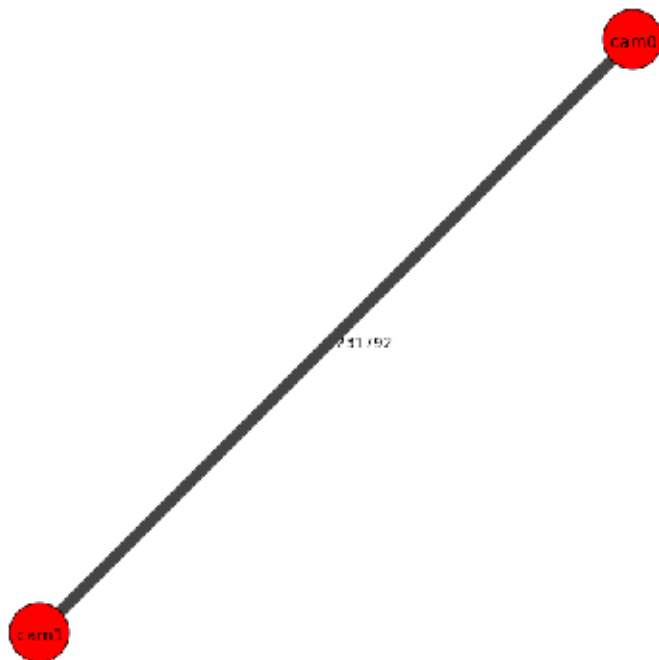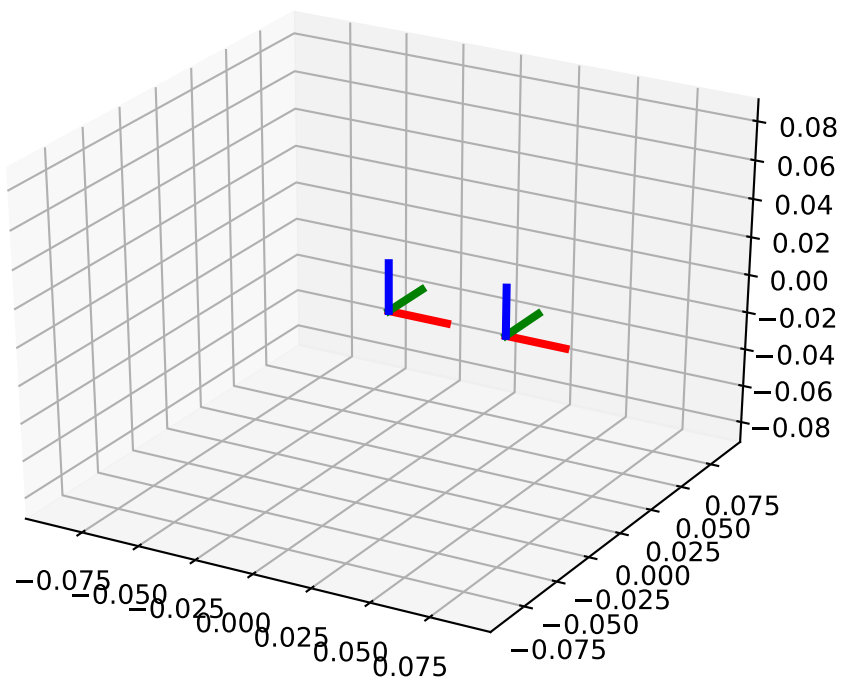Type: checkerboard
Rows
Count: 11
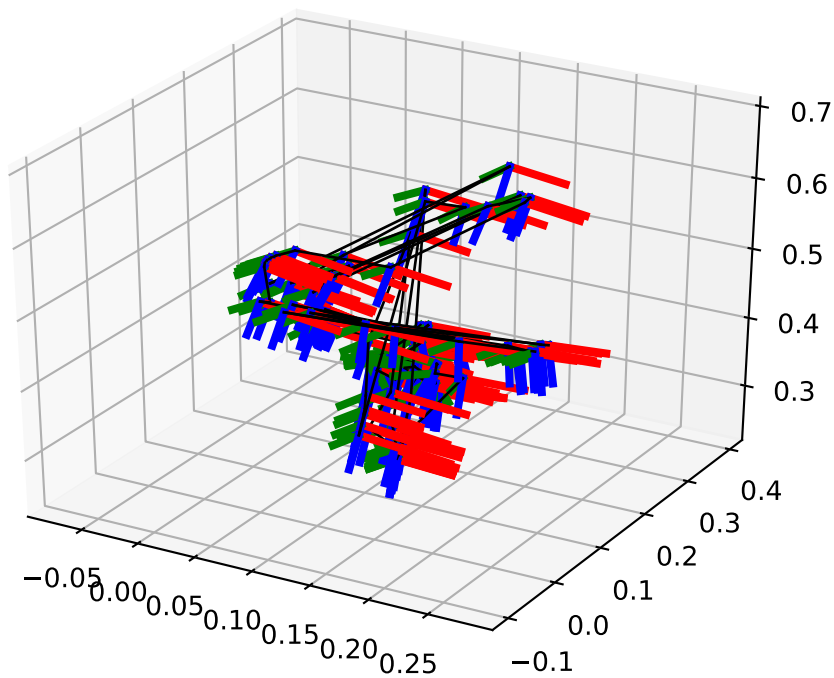Distance: 0.02 [m]
Cols
Count: 8
Distance: 0.02 [m]

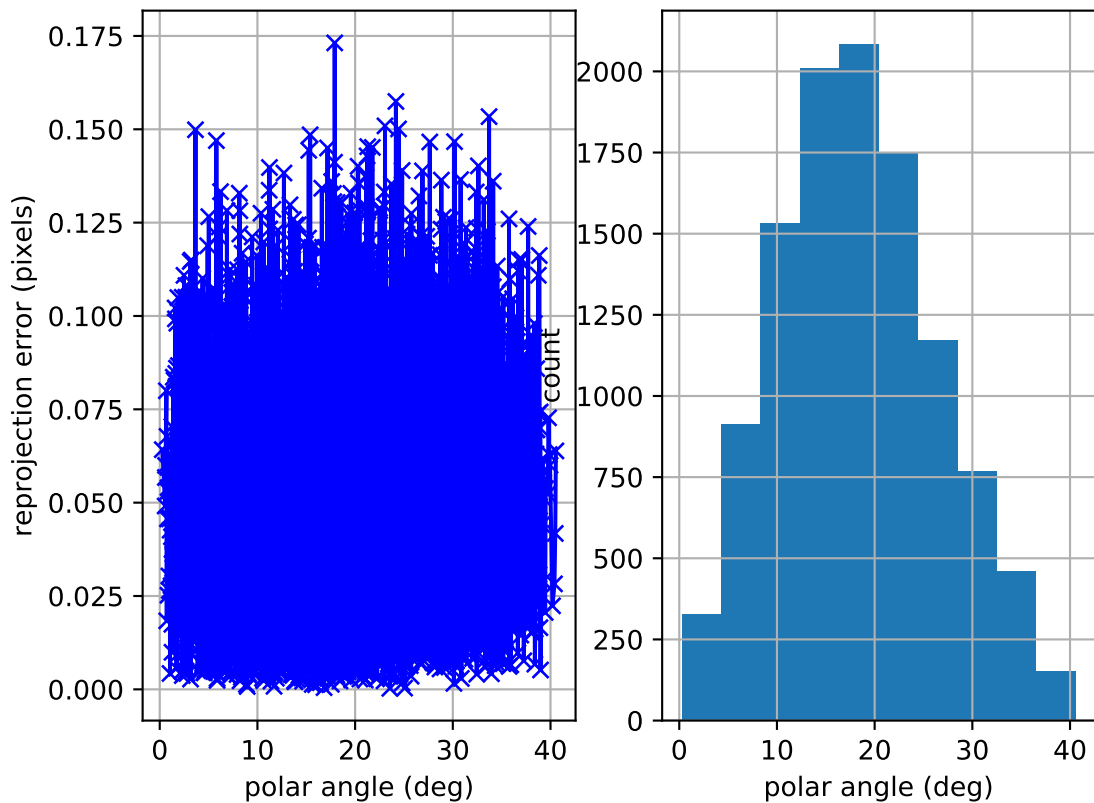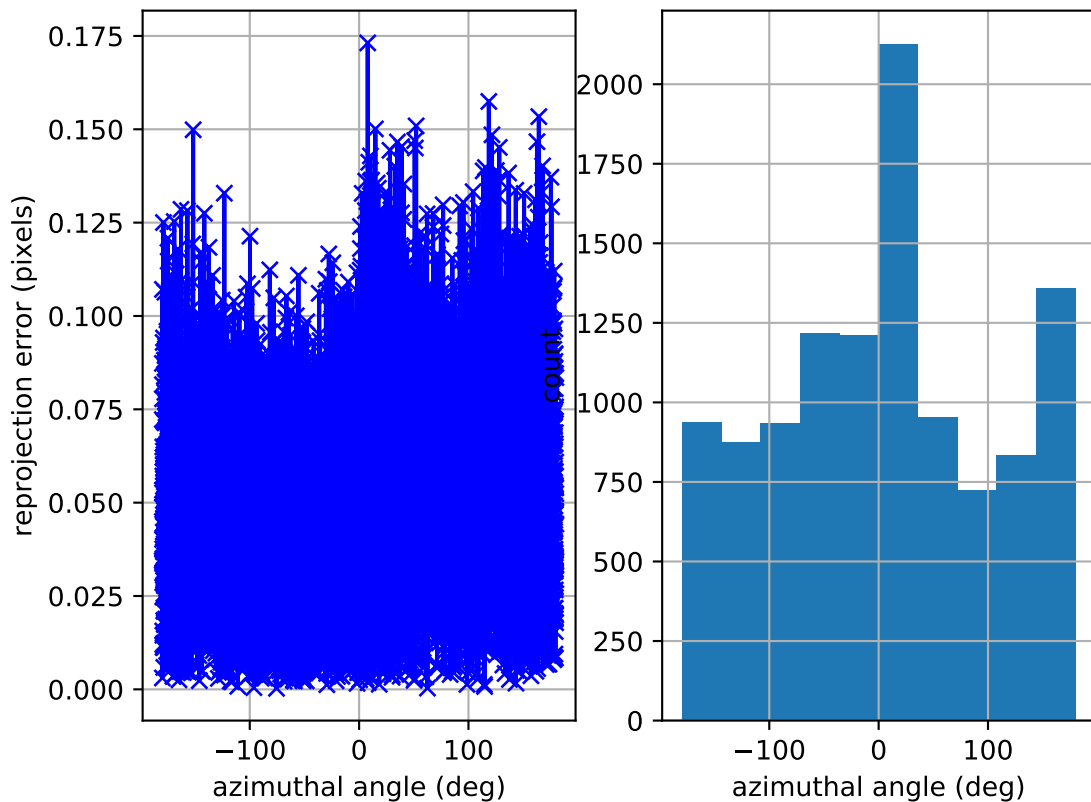Inter-camera observations graph (edge weight=#mutual obs.)
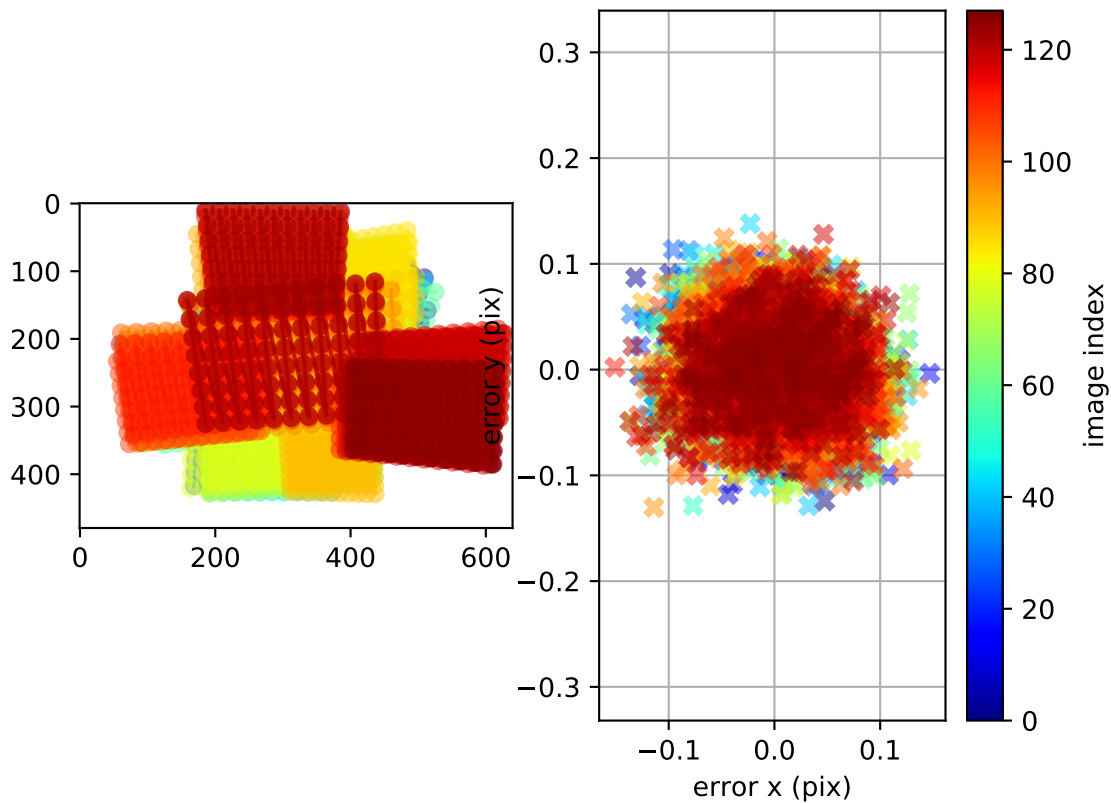
camera system

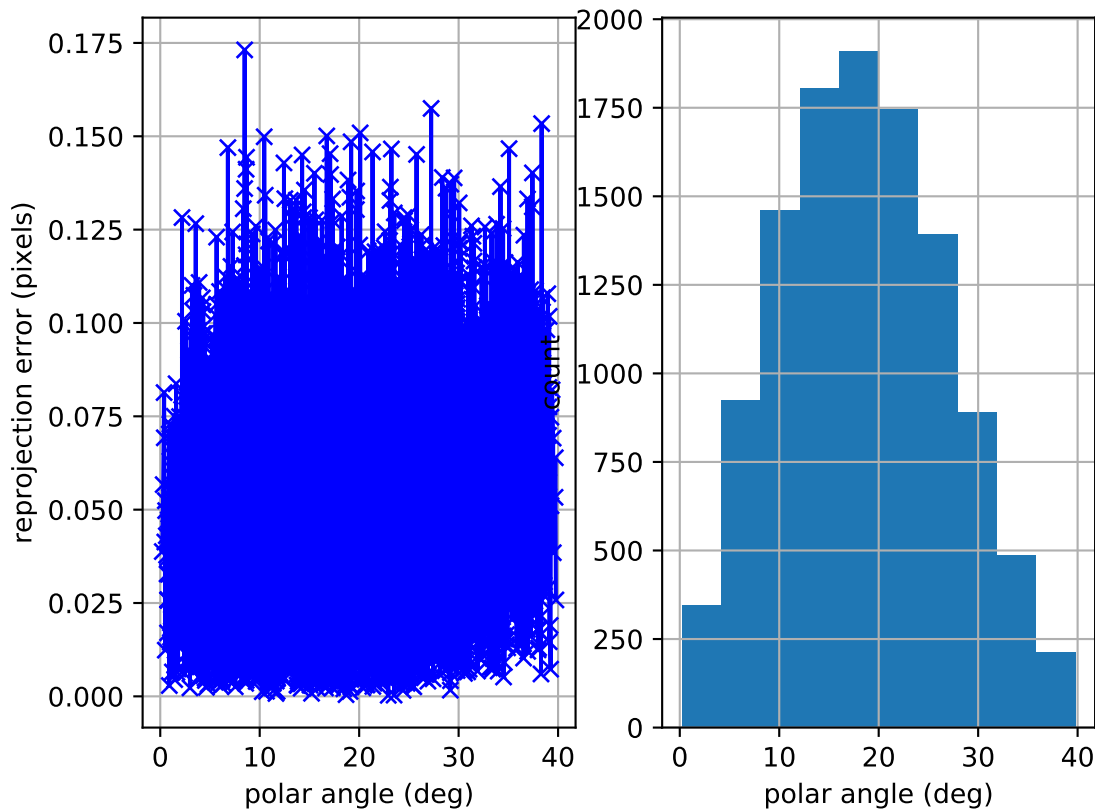cam0: estimated poses

cam0: polar error

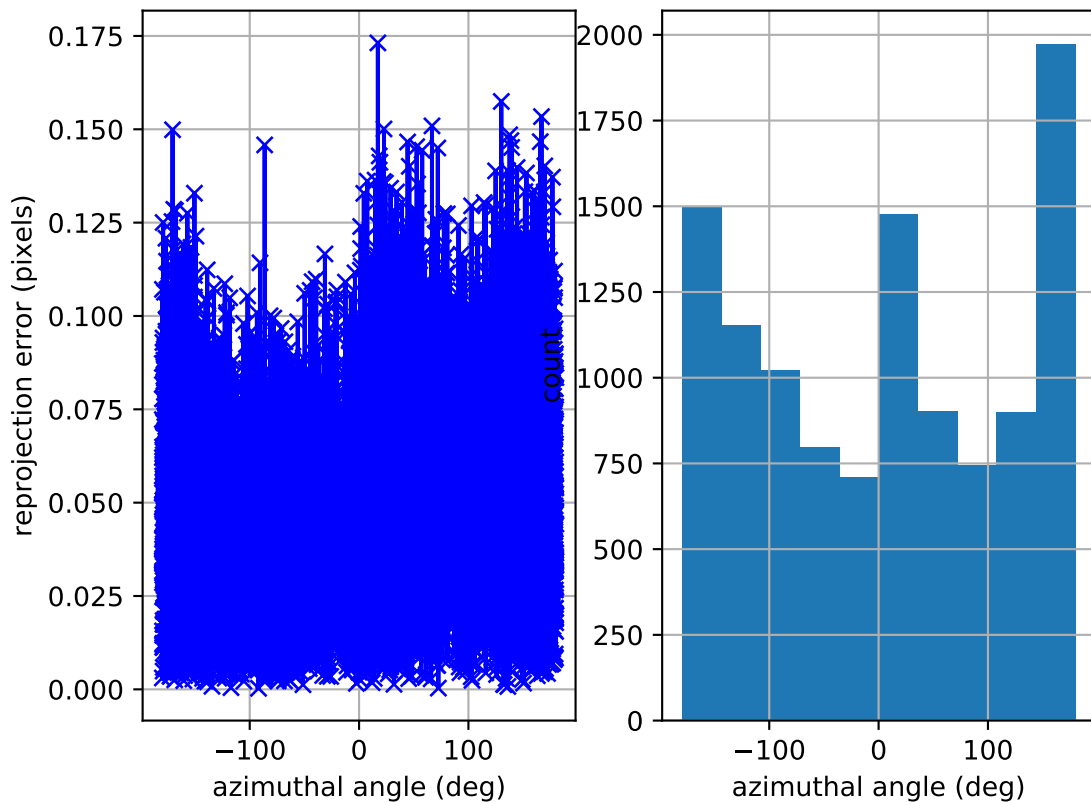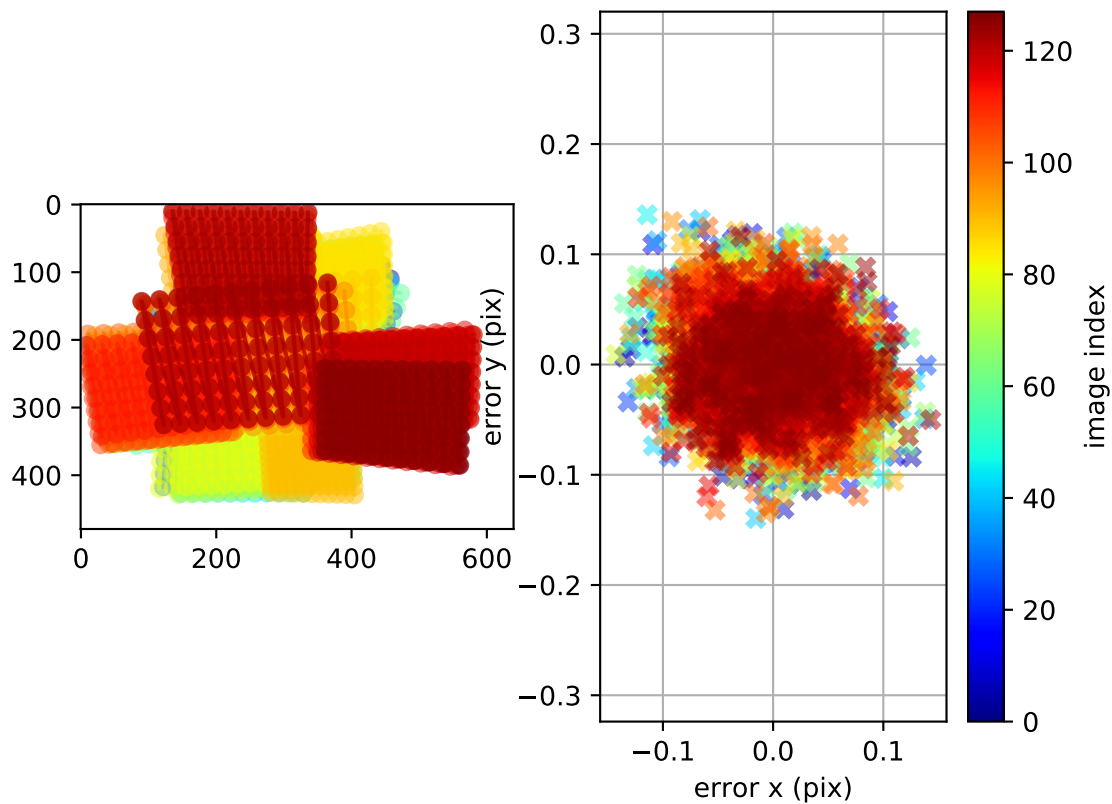cam0: azimuthal error

cam0: reprojection errors
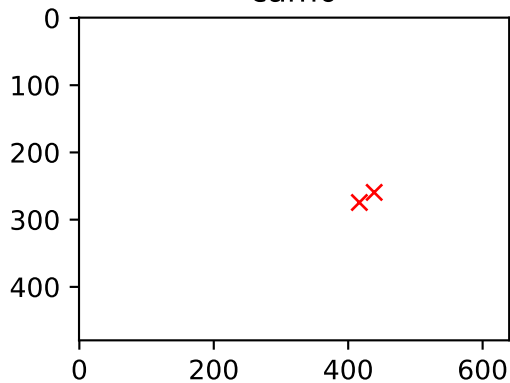
cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners