Calibration results
====================
Camera-system parameters:
cam0 (/ifo002/camera/infra1/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [-0.00063259 0.00047558 -0.00036145 0.00010234] +- [0.00073282 0.00057204 0.00018859 0.00023086]
projection: [420.32934241 422.09385633 427.46982183 235.96662924] +- [0.57065411 0.55947926 0.43689116
0.385916]
reprojection error: [0.000003, 0.000000] +- [0.271059, 0.268206]

cam1 (/ifo002/camera/infra2/image_rect_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedPinholeCameraGeometry'>
distortion: [-0.00019974 0.00030013 -0.00041559 -0.0001946] +- [0.00072046 0.00054963 0.00019004 0.00023256]
projection: [420.33928766 422.11848957 427.52578253 236.10169089] +- [0.57088994 0.56081243 0.43913751
0.3871644]
reprojection error: [-0.000003, -0.000000] +- [0.266793, 0.265614]

baseline T_1_0:
q: [-0.00013939 -0.00054541 0.00003909 0.99999984] +- [0.0003472   0.00069233 0.00006093]
t: [-0.04998315 0.00000413 0.00002004] +- [0.00006102 0.00006052 0.00013757]

Target configuration
=====================
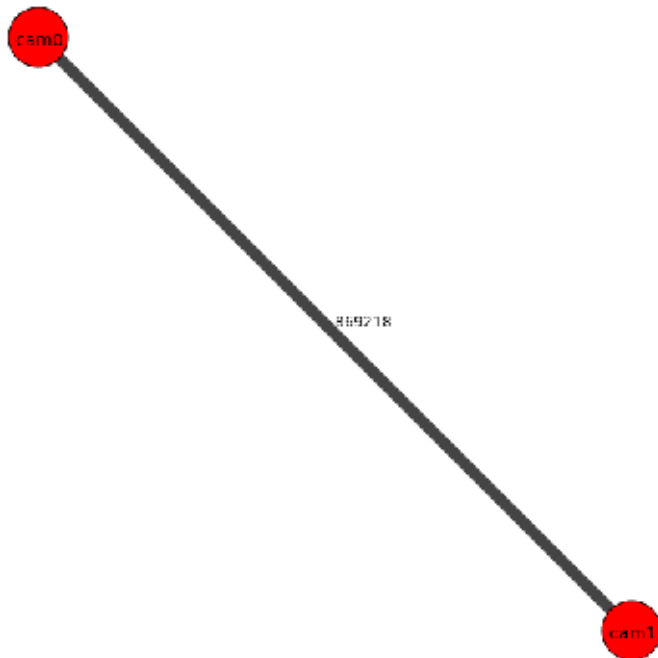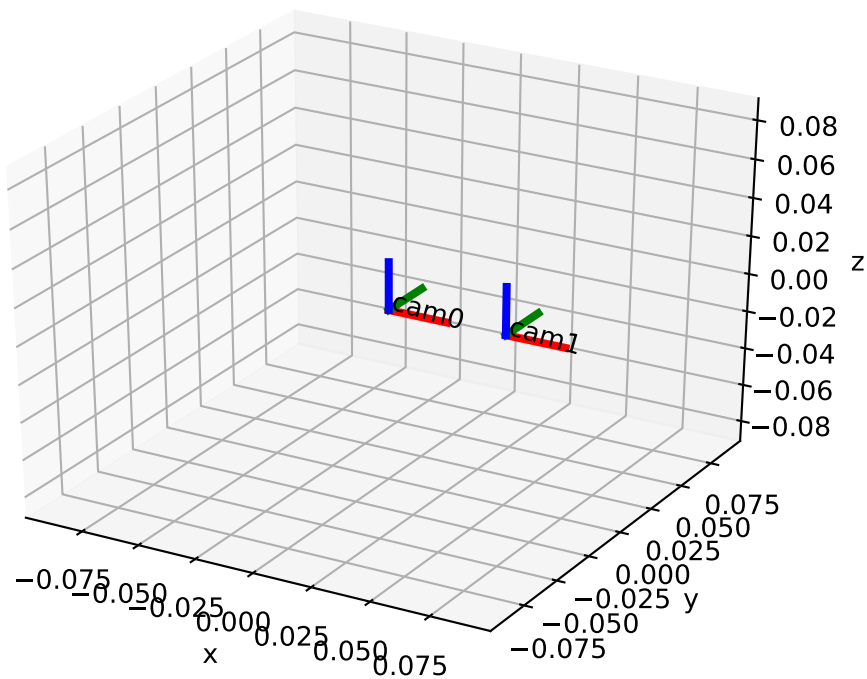
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0625 [m]
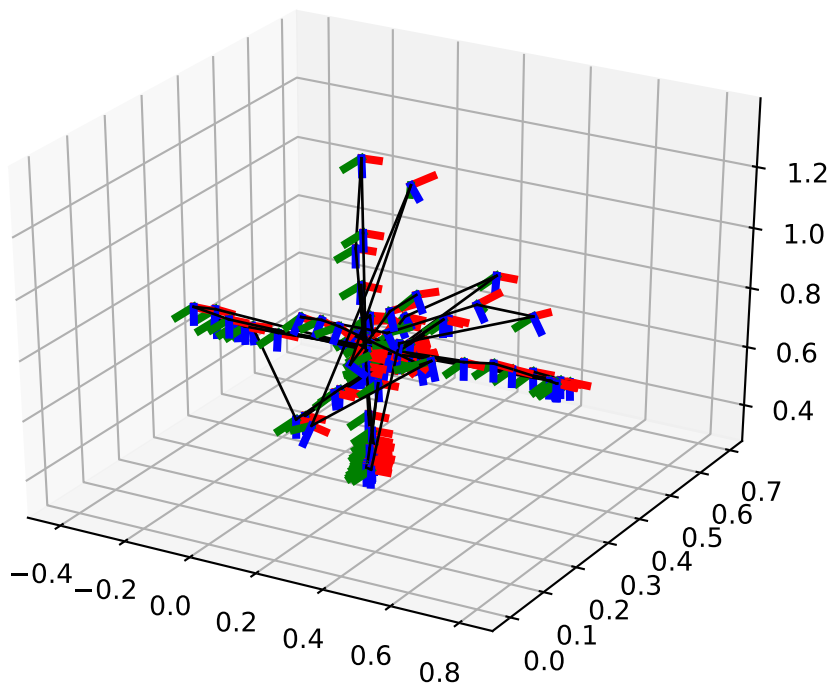Spacing 0.01875 [m]

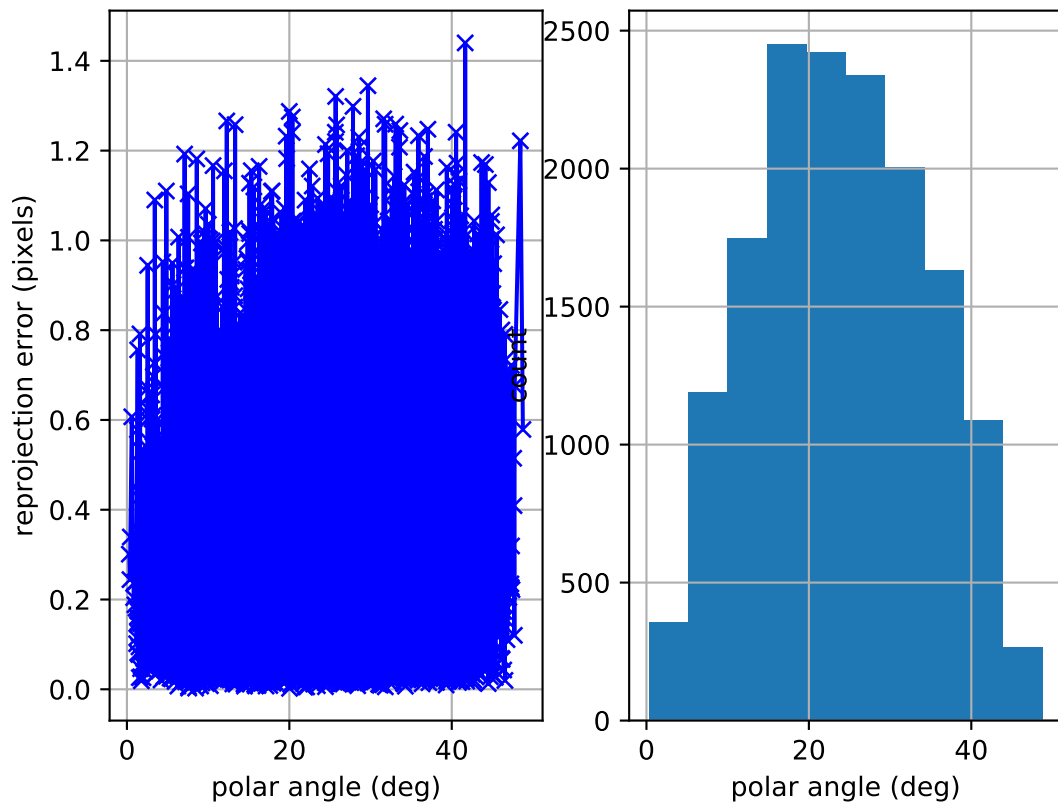Inter-camera observations graph (edge weight=#mutual obs.)
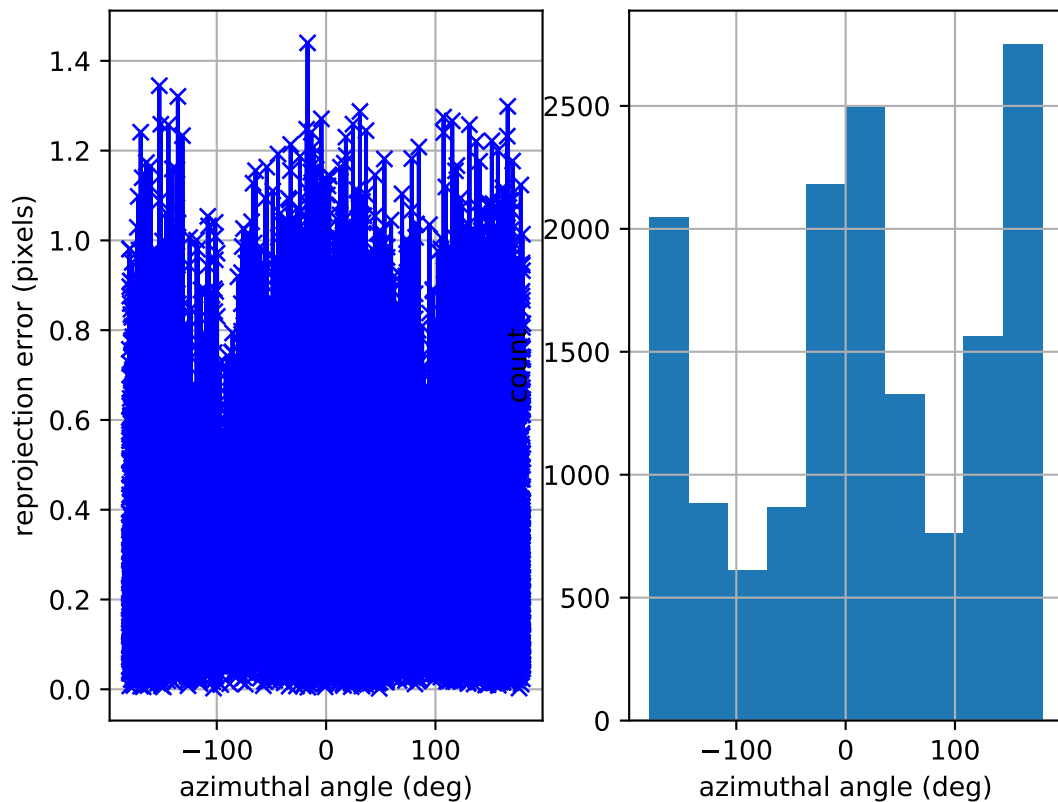
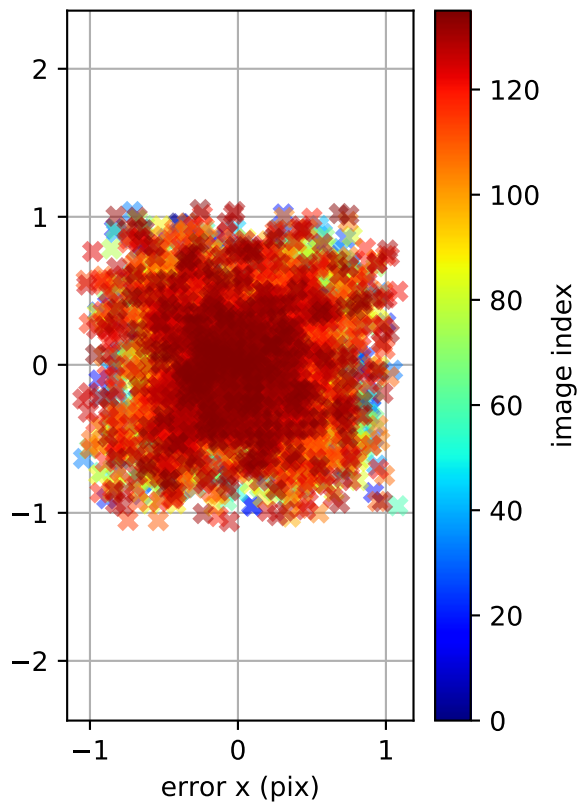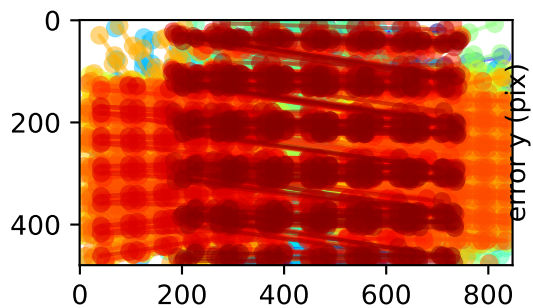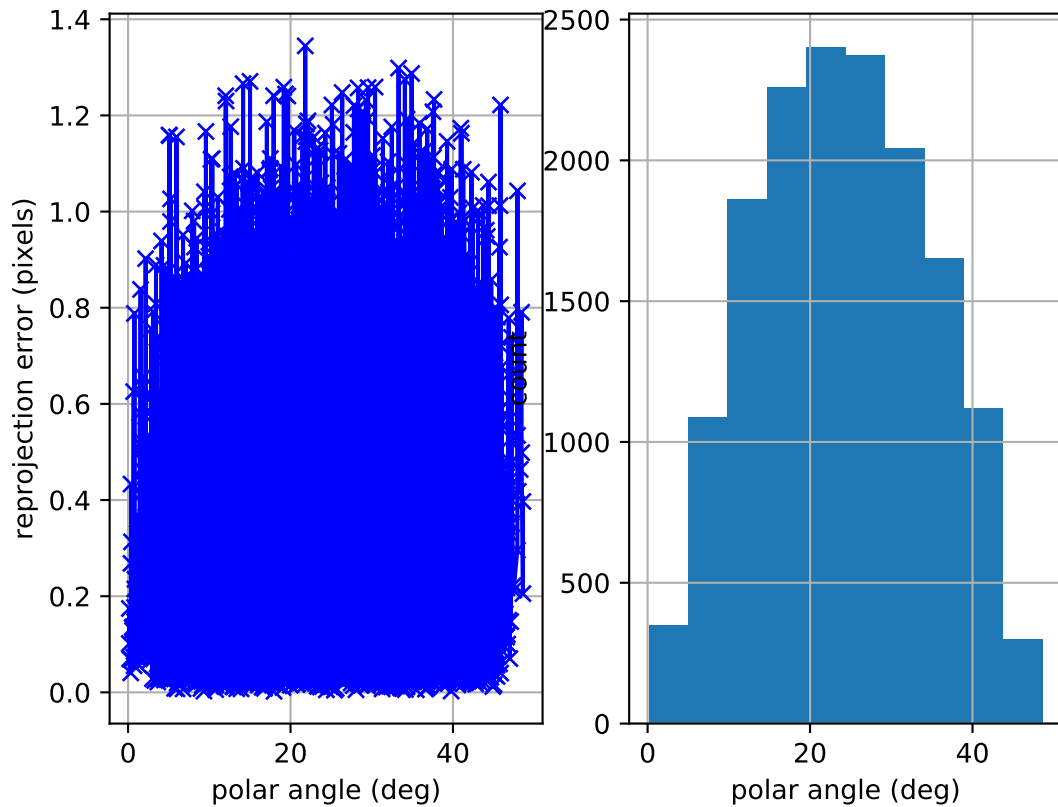camera system

cam0: estimated poses

cam0: polar error
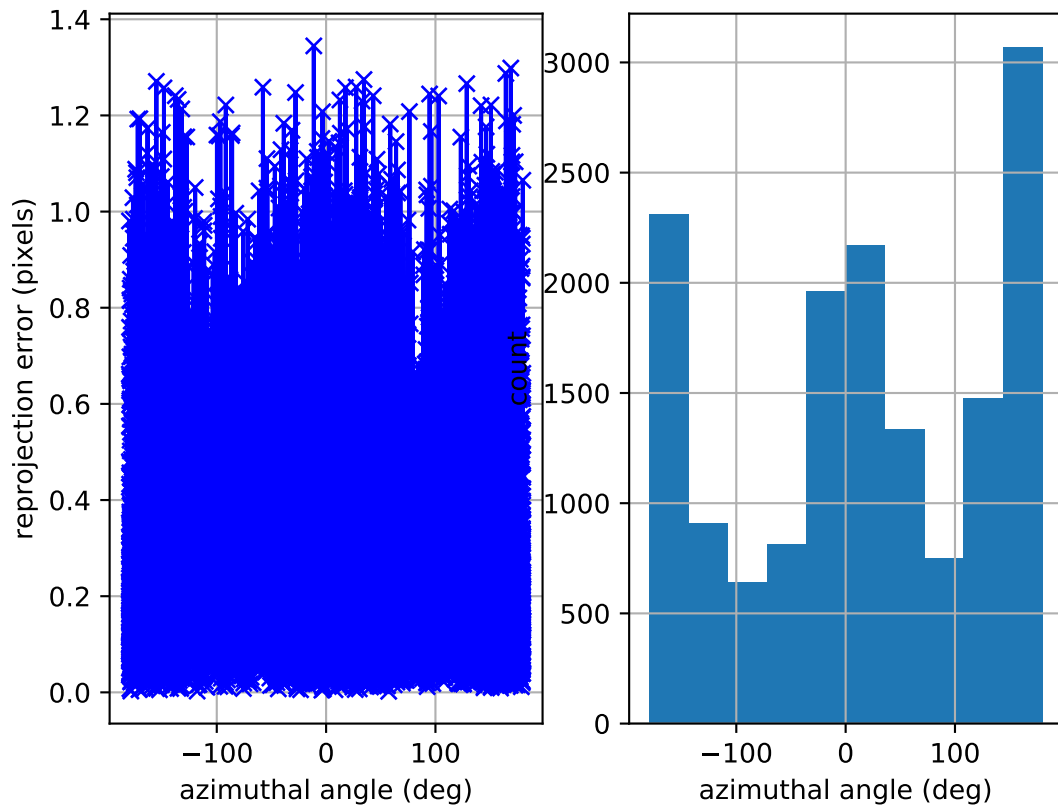
cam0: azimuthal error

cam0: reprojection errors
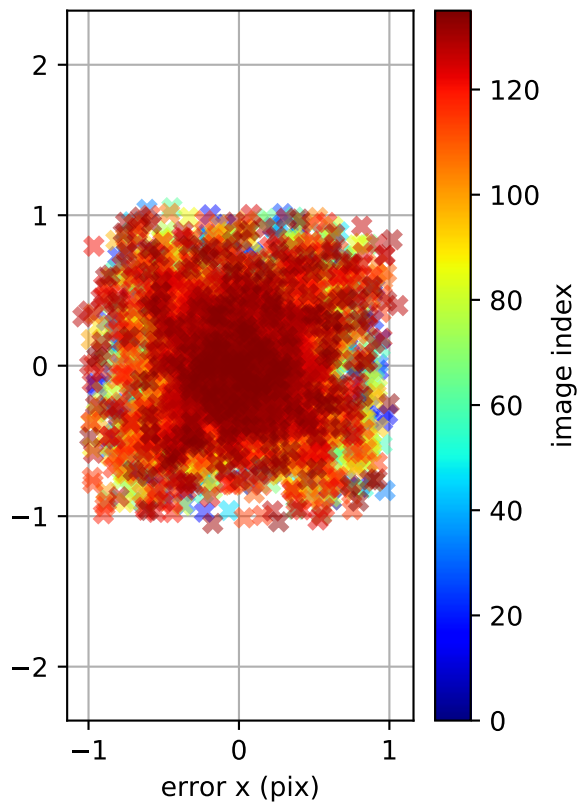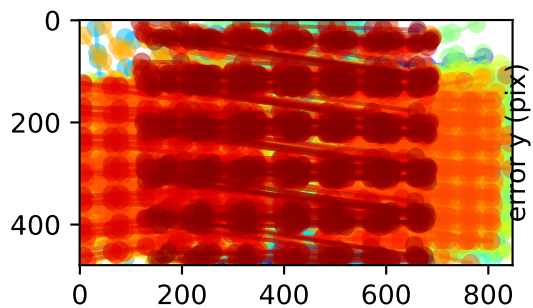
cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners