Calibration results
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Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [-0.01376546 0.02168872 -0.02002828 0.00939944] +- [0.0064409   0.02913654 0.0501542   0.02936513]
projection: [289.36034236 290.13607275 316.15159346 200.79298863] +- [0.02905431 0.0275663   0.25044686
0.12577805]
reprojection error: [-0.000003, 0.000004] +- [0.122112, 0.114395]

cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.EquidistantDistortedPinholeCameraGeometry'>
distortion: [-0.02184828 0.0465897 -0.03960693 0.01115653] +- [0.00555599 0.02225189 0.03420726 0.01781831]
projection: [289.20367592 289.98114733 315.88386957 199.90524803] +- [0.02831477 0.03080107 0.23870666
0.12945301]
reprojection error: [-0.000004, 0.000004] +- [0.126256, 0.112969]

baseline T_1_0:
q: [-0.00226937 -0.00627098 -0.01216897 0.99990372] +- [0.00061901 0.0009923   0.00009555]
t: [-0.08043923 0.00008173 0.0000429] +- [0.00011509 0.00010629 0.00020889]

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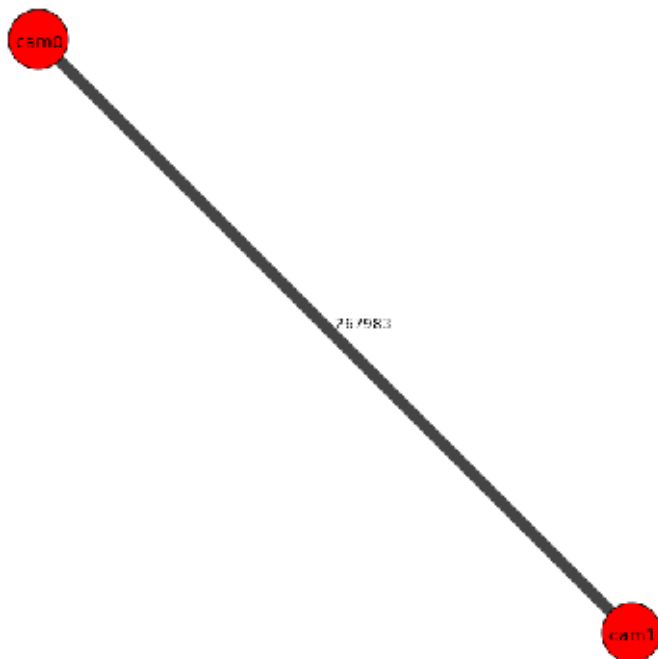====================

Type: aprilgrid
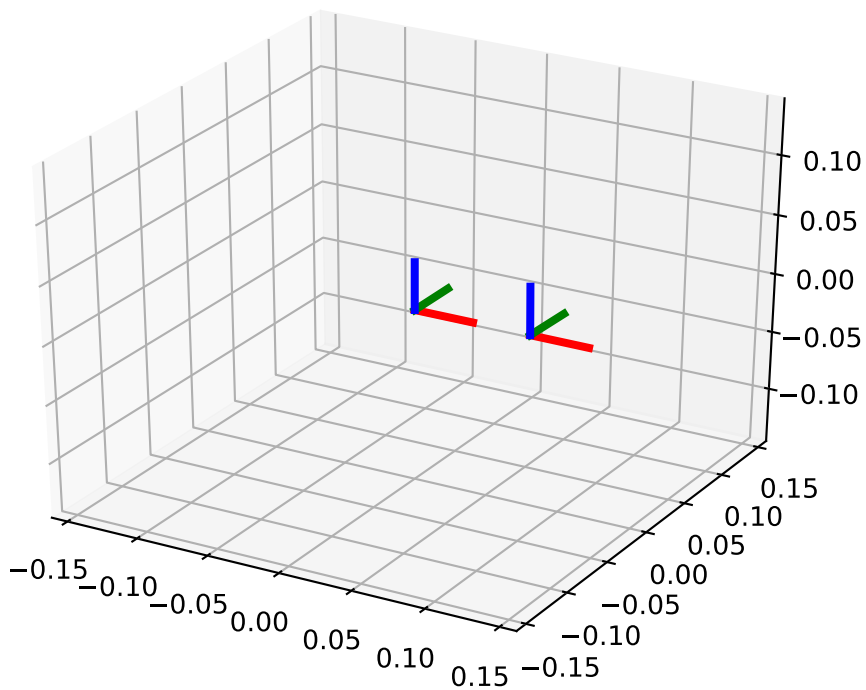Tags:
Rows: 6
Cols: 6
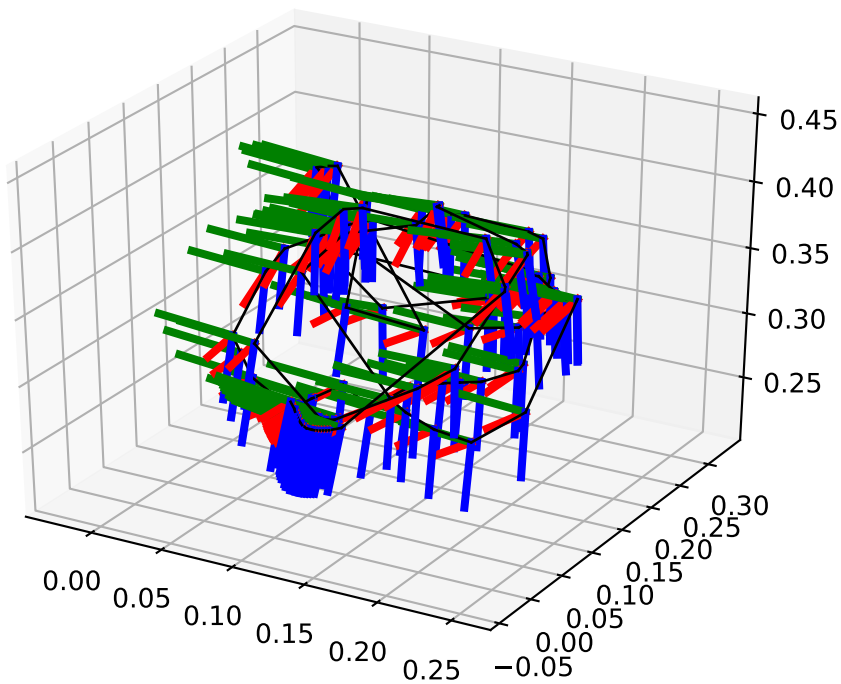Size: 0.0312 [m]
Spacing 0.00959999976 [m]

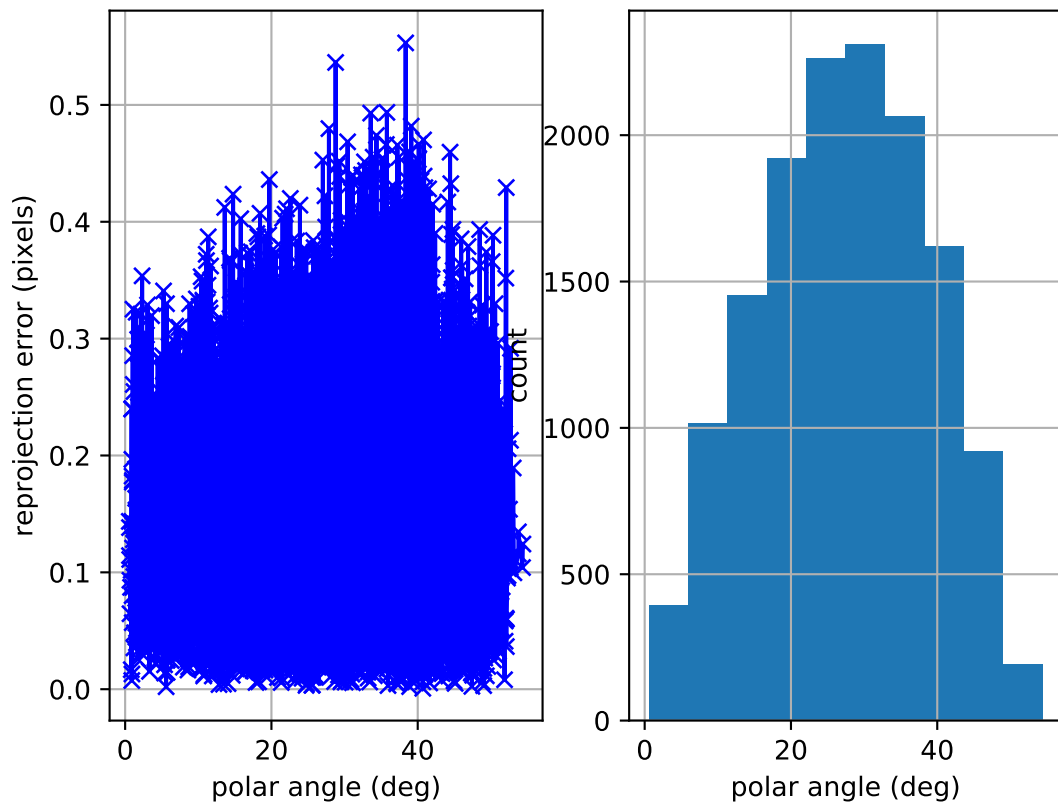# Inter-camera observations graph (edge weight=#mutual obs.)
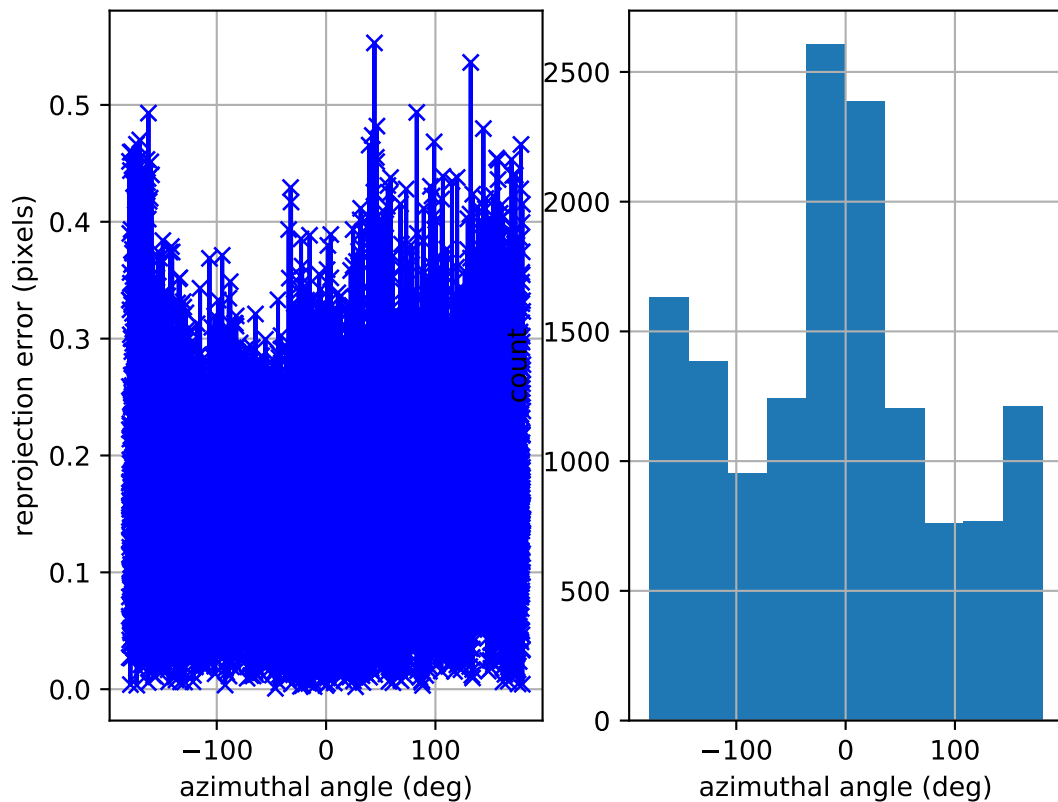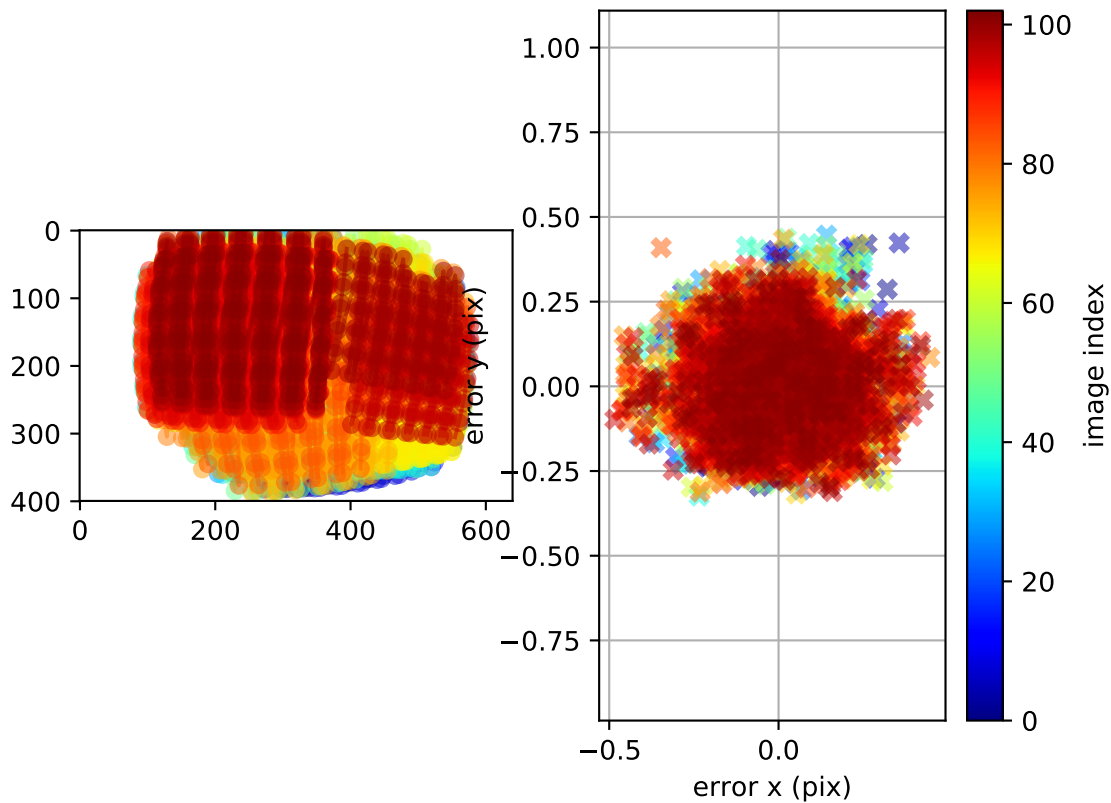
camera system
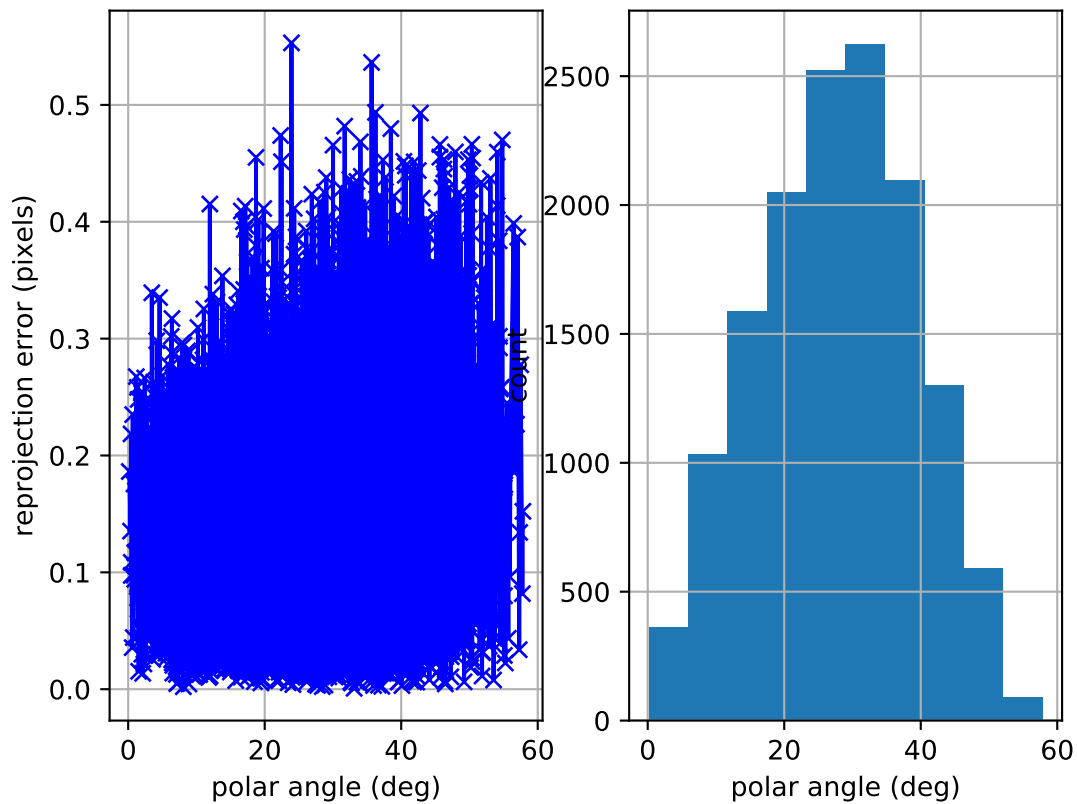
cam0: estimated poses

cam0: polar error
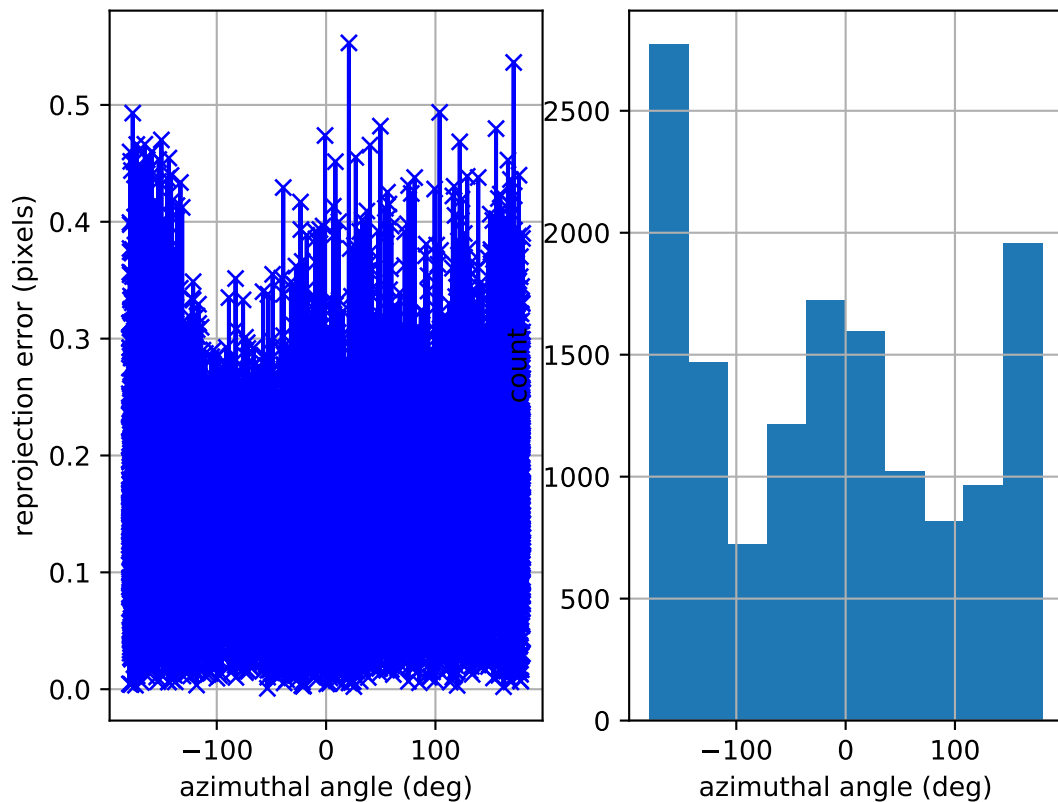
cam0: azimuthal error
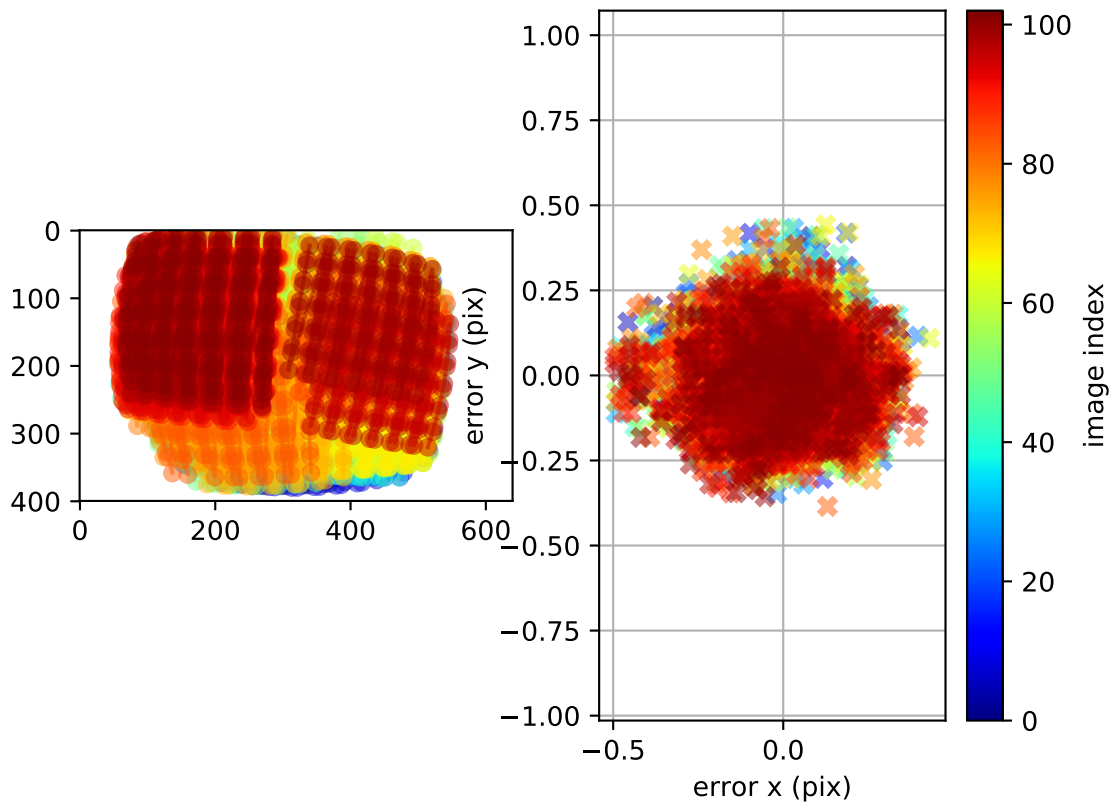
cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners