Calibration results
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Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.OmniCameraGeometry'>
distortion: [] +- []
projection: [1.80855472 796.15915548 798.54206835 314.24122811 200.88208336] +- [0.00686073 2.8940867
2.83831082 0.36659817 0.33525577]
reprojection error: [-0.000004, 0.000000] +- [0.134145, 0.117805]

cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.OmniCameraGeometry'>
distortion: [] +- []
projection: [1.80247821 792.56553328 794.39482967 313.43049624 200.09075464] +- [0.00677663 3.02763726
2.95378899 0.36336583 0.33962222]
reprojection error: [0.000003, -0.000000] +- [0.130701, 0.110050]

baseline T_1_0:
q: [-0.00315457 0.0055156   0.00800251 0.99994779] +- [0.00067733 0.00111855 0.00015049]
t: [0.08068222 -0.00156068 0.000102] +- [0.00017746 0.00015819 0.00047519]

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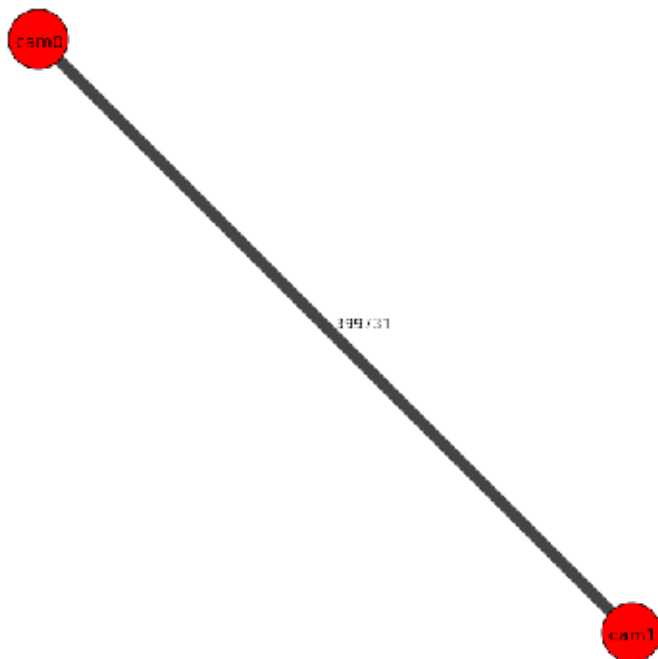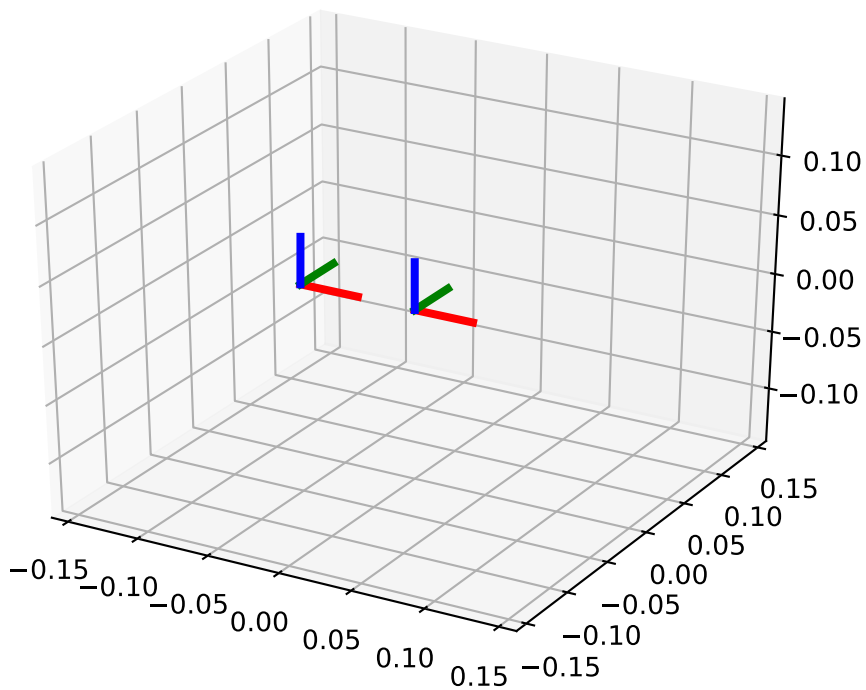====================

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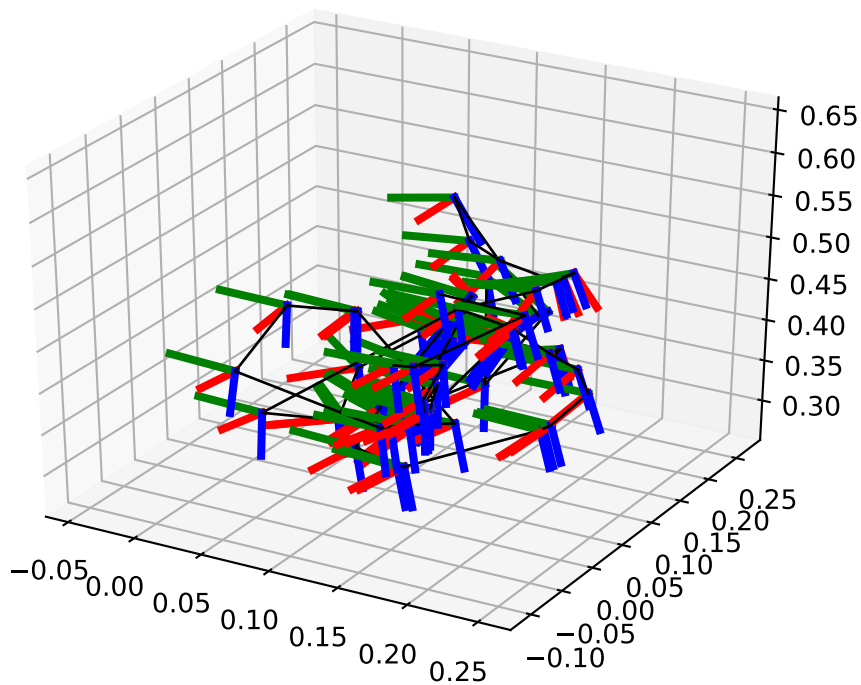Size: 0.0312 [m]
Spacing 0.00959999976 [m]

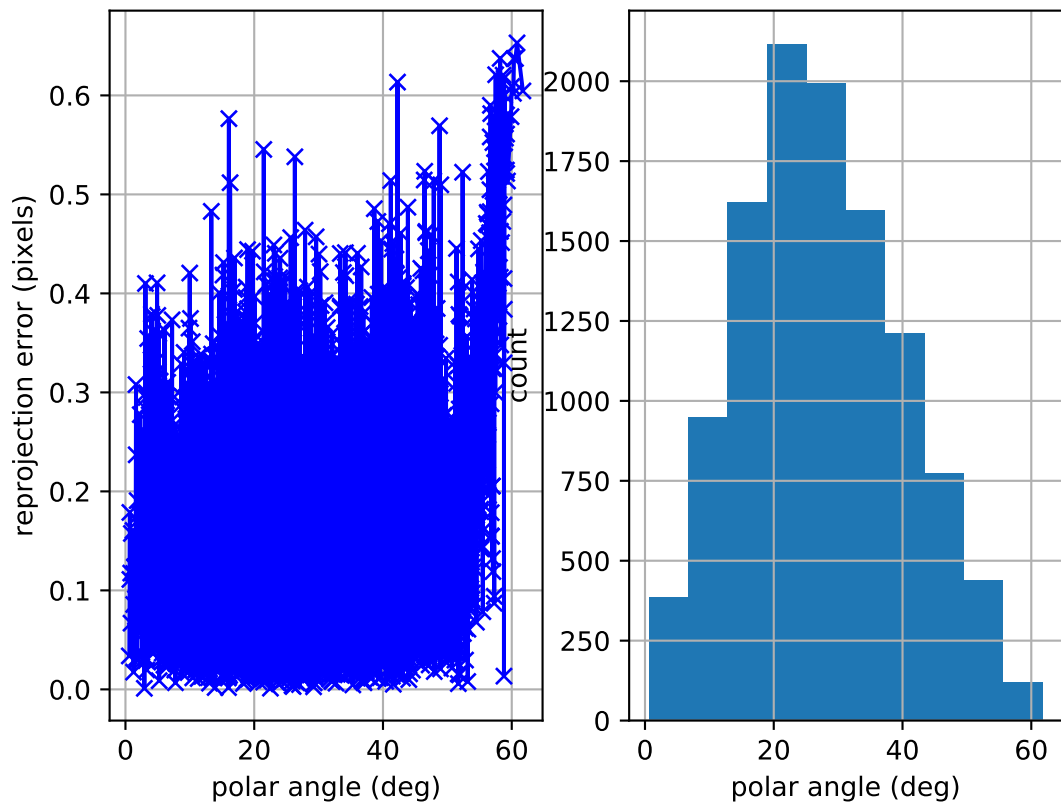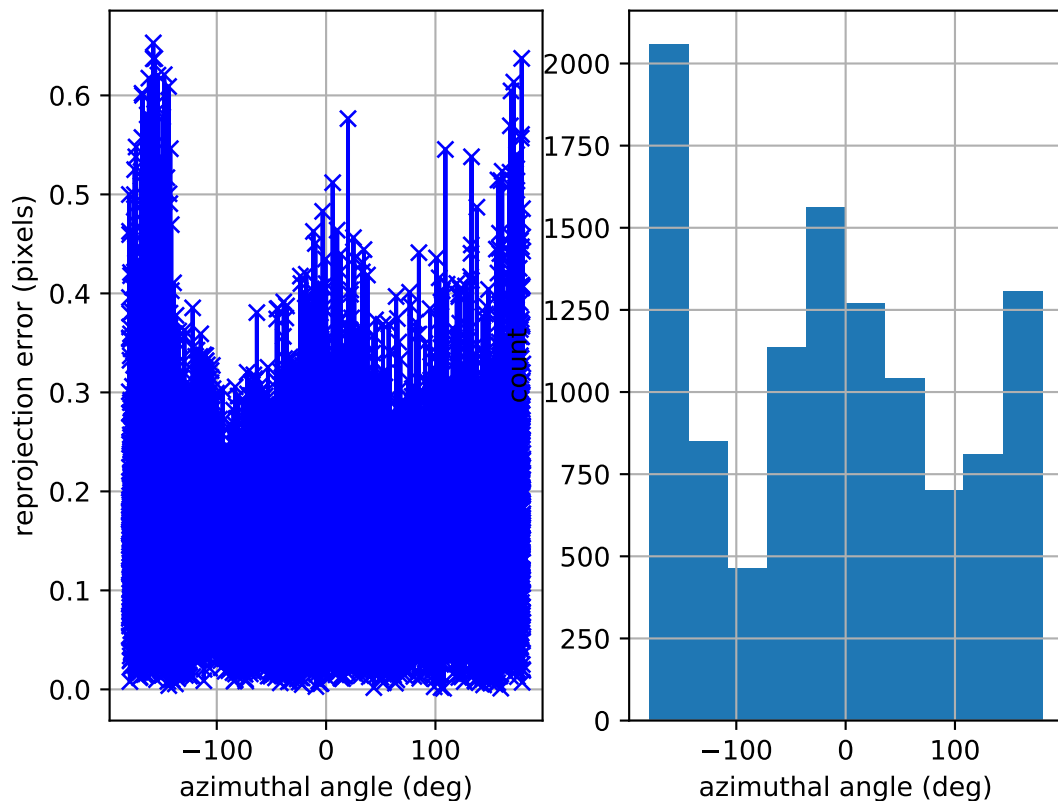Inter-camera observations graph (edge weight=#mutual obs.)
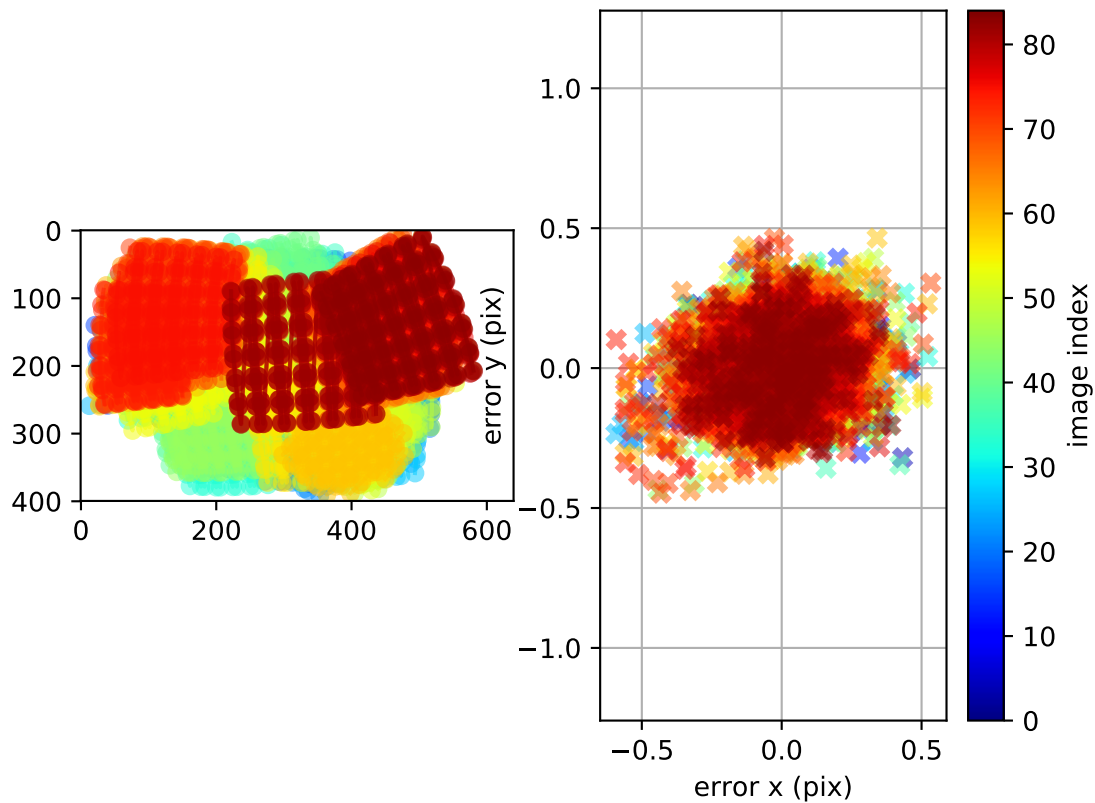
camera system

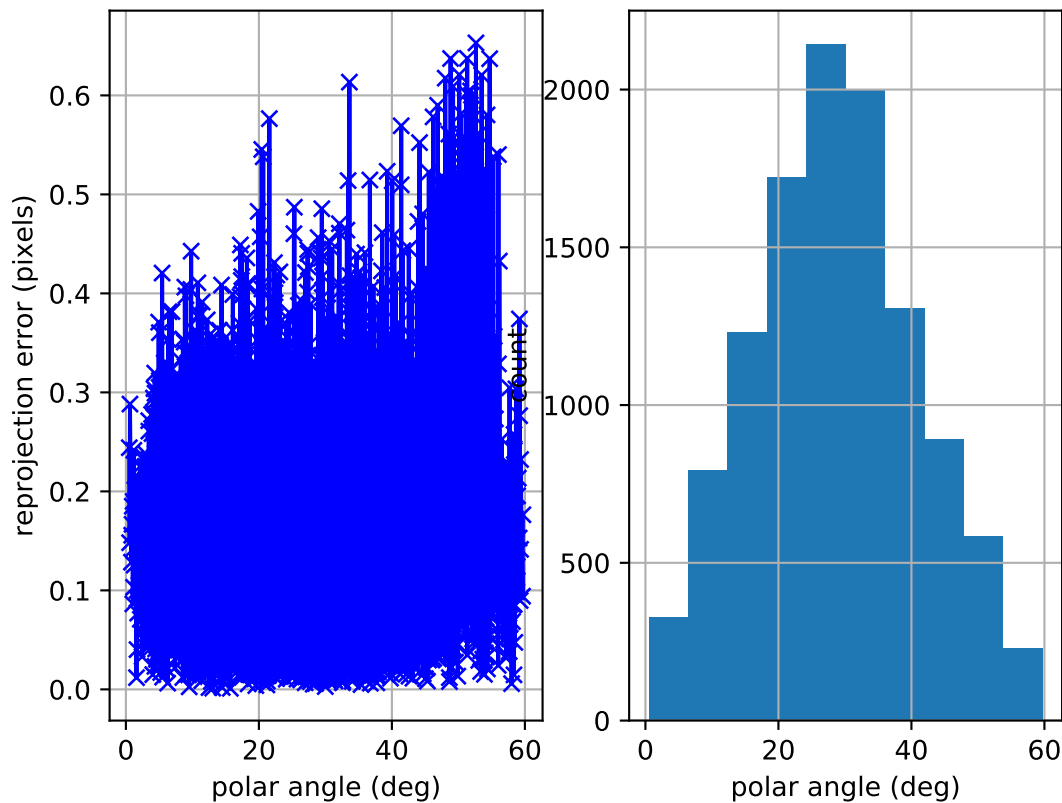cam0: estimated poses

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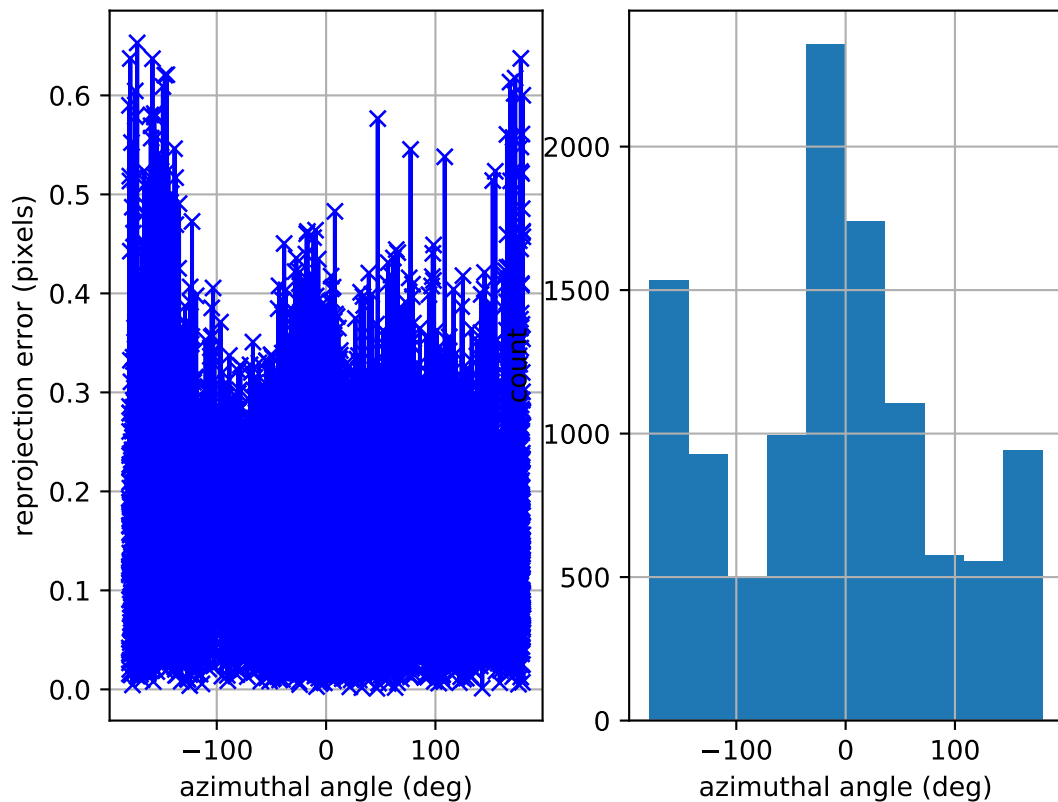
cam0: azimuthal error
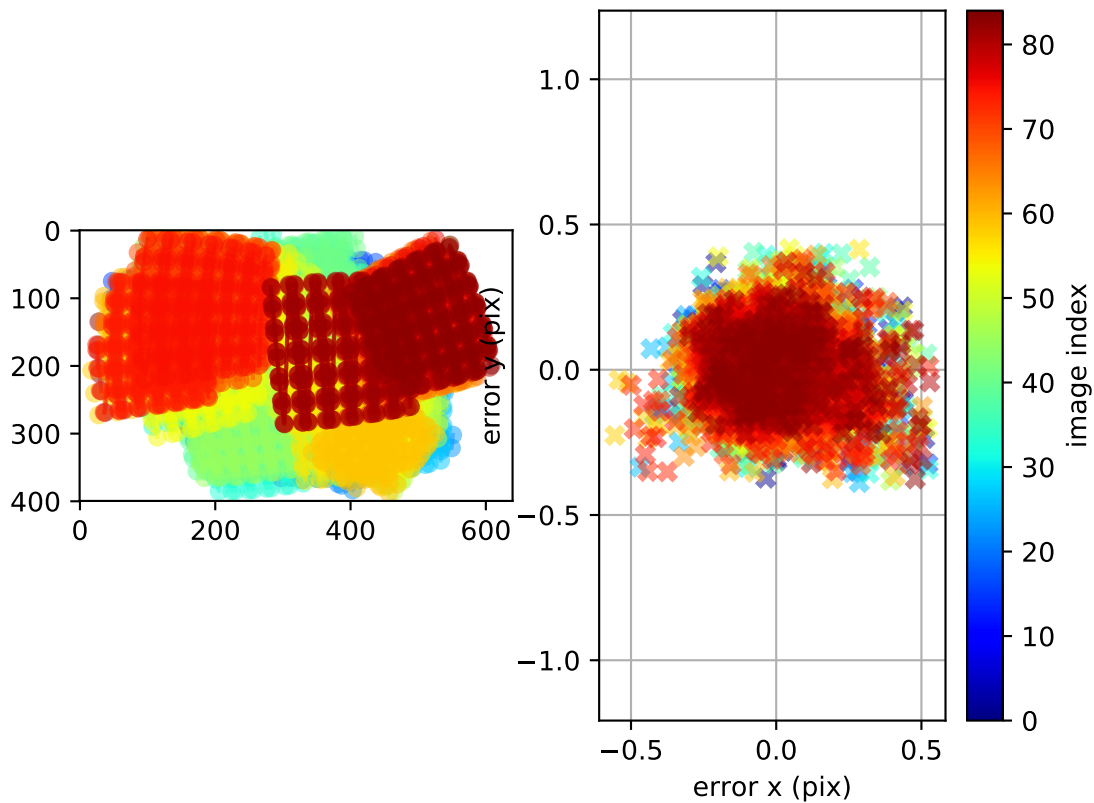
cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners