Calibration results
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Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DoubleSphereCameraGeometry'>
distortion: [] +- []
projection: [  -0.30221382    0.54951149  200.86134734  201.14091548  315.62323867
199.04803515] +- [ 0.00151885  0.00045872  0.03774786  0.03621404  0.45849315  0.39560073]
reprojection error: [-0.000007, 0.000002] +- [0.098029, 0.092074]

cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DoubleSphereCameraGeometry'>
distortion: [] +- []
projection: [  -0.3029009    0.5484217  200.64308518  201.01427866  315.34443737
198.16793088] +- [ 0.00103986  0.00039407  0.04260945  0.0369852   0.47141628  0.38189794]
reprojection error: [0.000001, -0.000000] +- [0.099369, 0.098147]

baseline T_1_0:
q: [-0.00191474 -0.0062407  -0.01176852  0.99990944] +- [ 0.00074271  0.00159877  0.0001721 ]
t: [-0.08042608 -0.00010447  0.00086599] +- [ 0.00024383  0.00023427  0.00060314]



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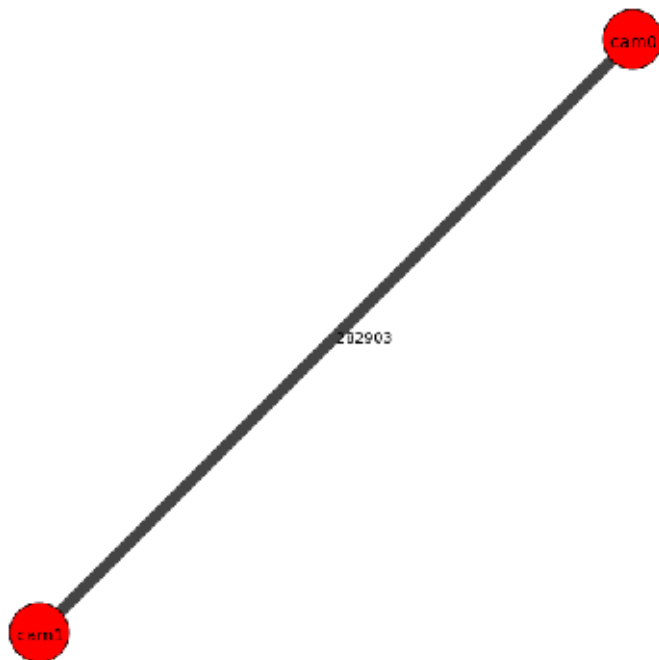====================

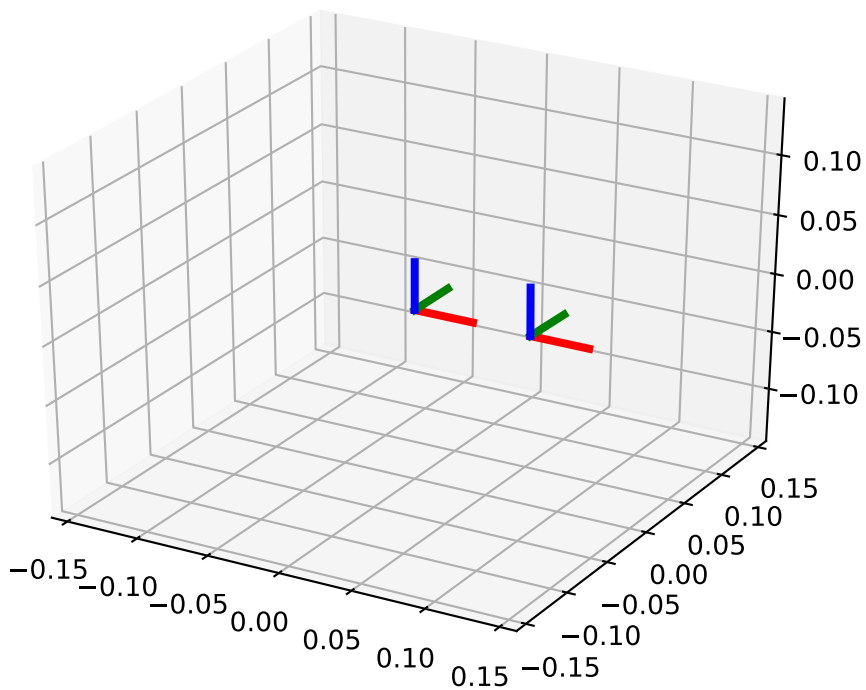Type: aprilgrid
Tags:
Rows: 6
Cols: 6
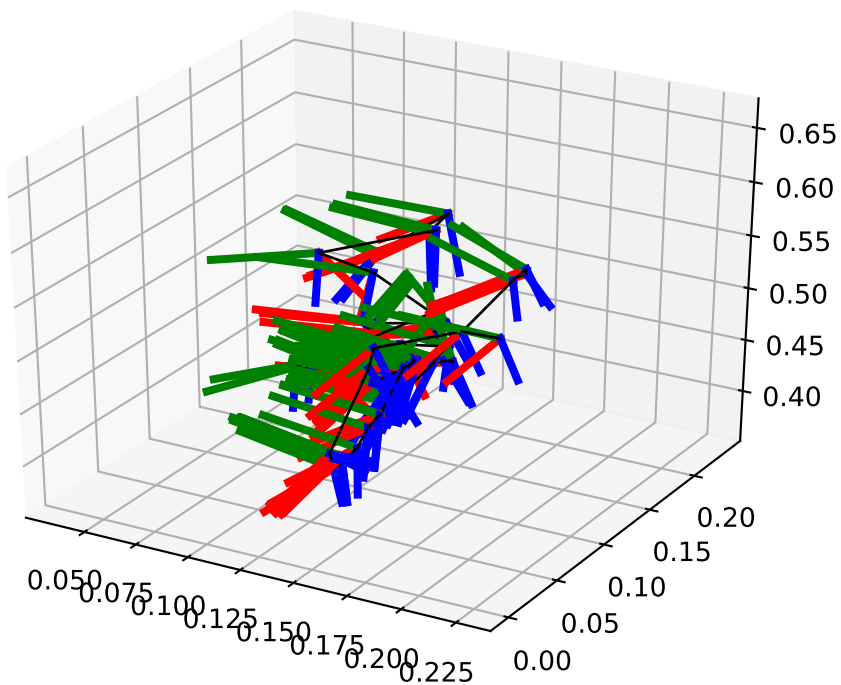Size: 0.0312 [m]
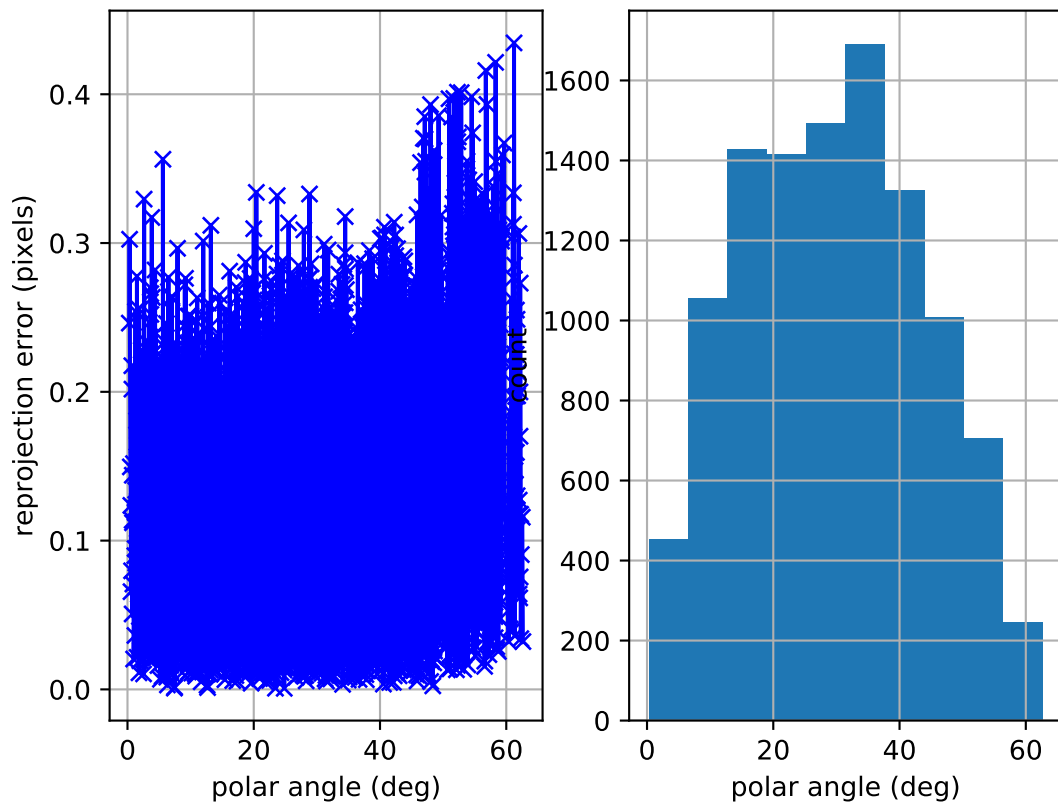Spacing 0.00959999976 [m]

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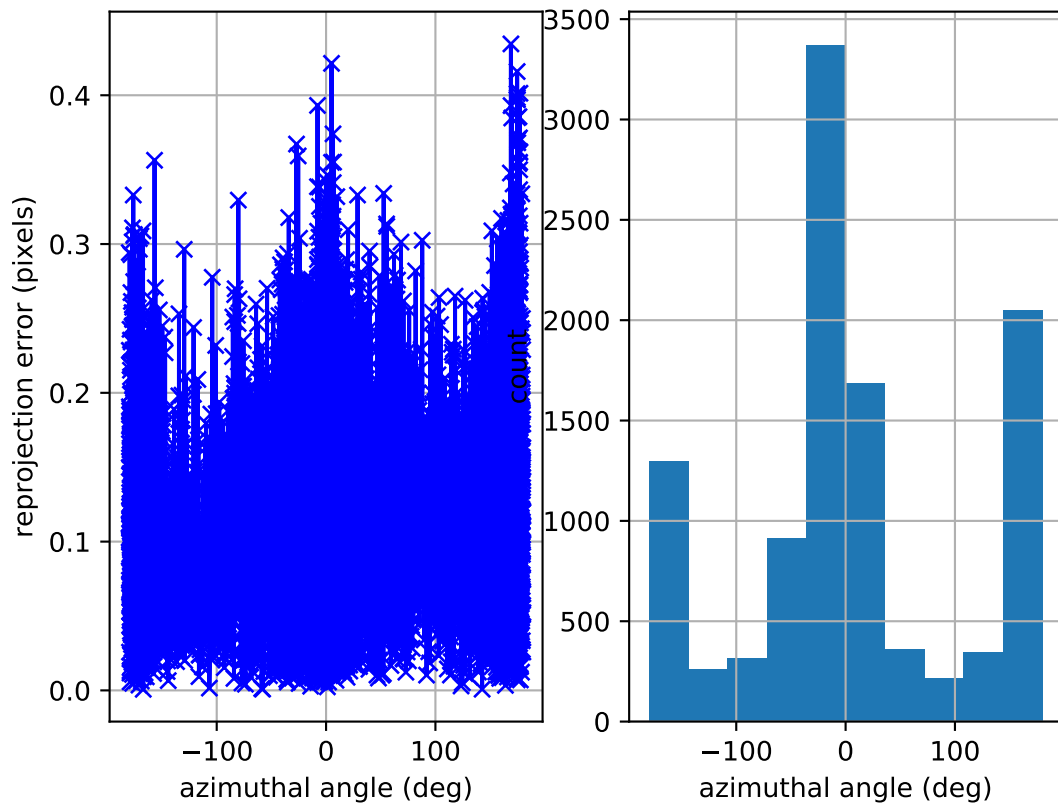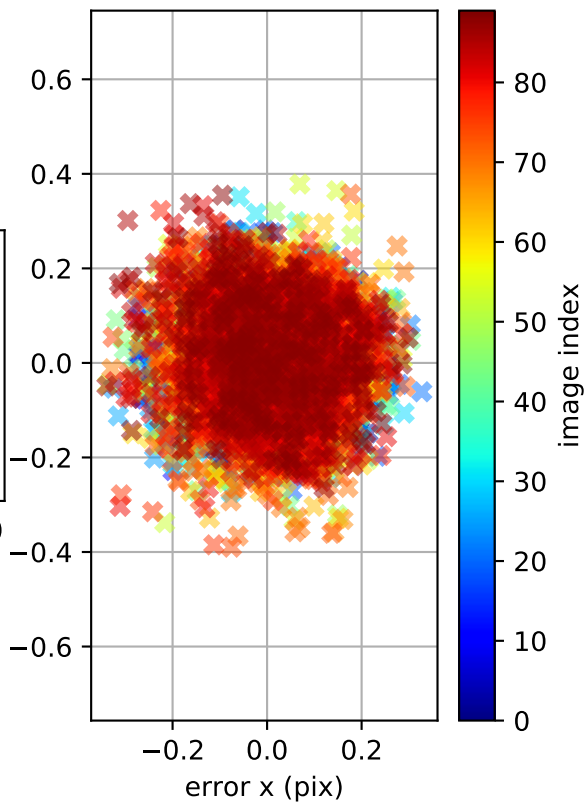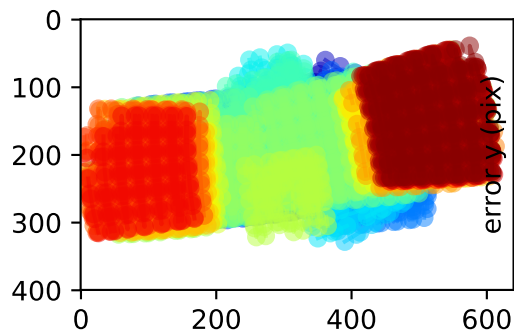
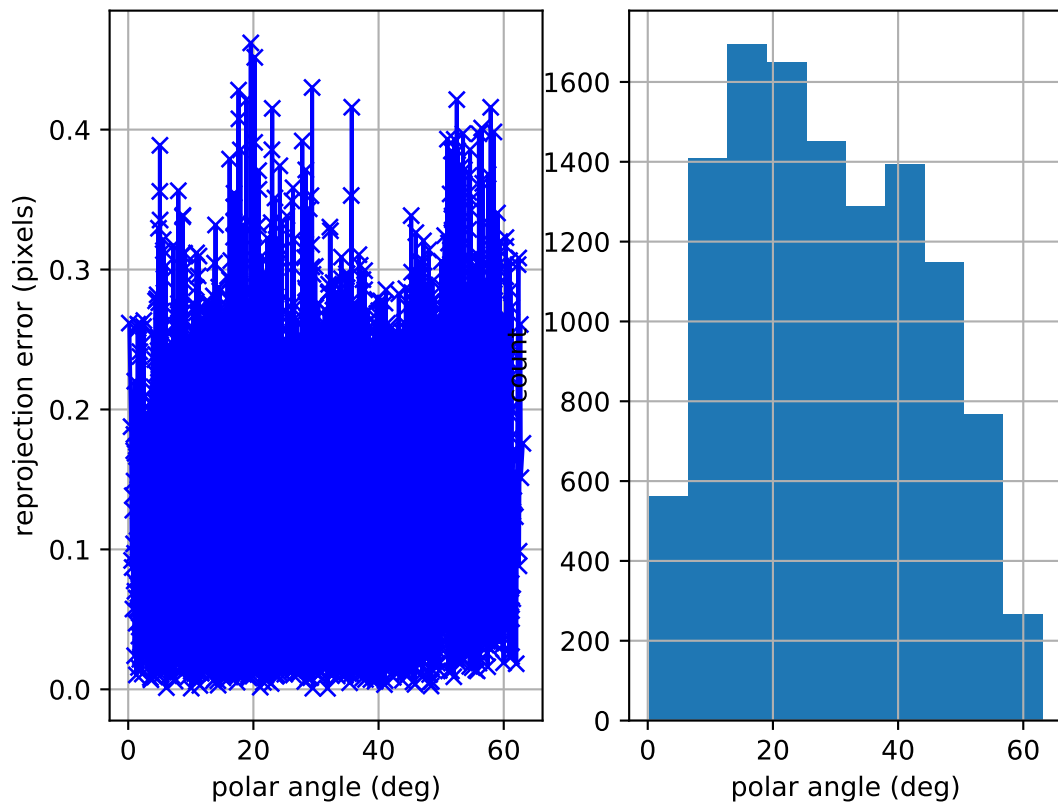camera system

cam0: estimated poses

cam0: polar error

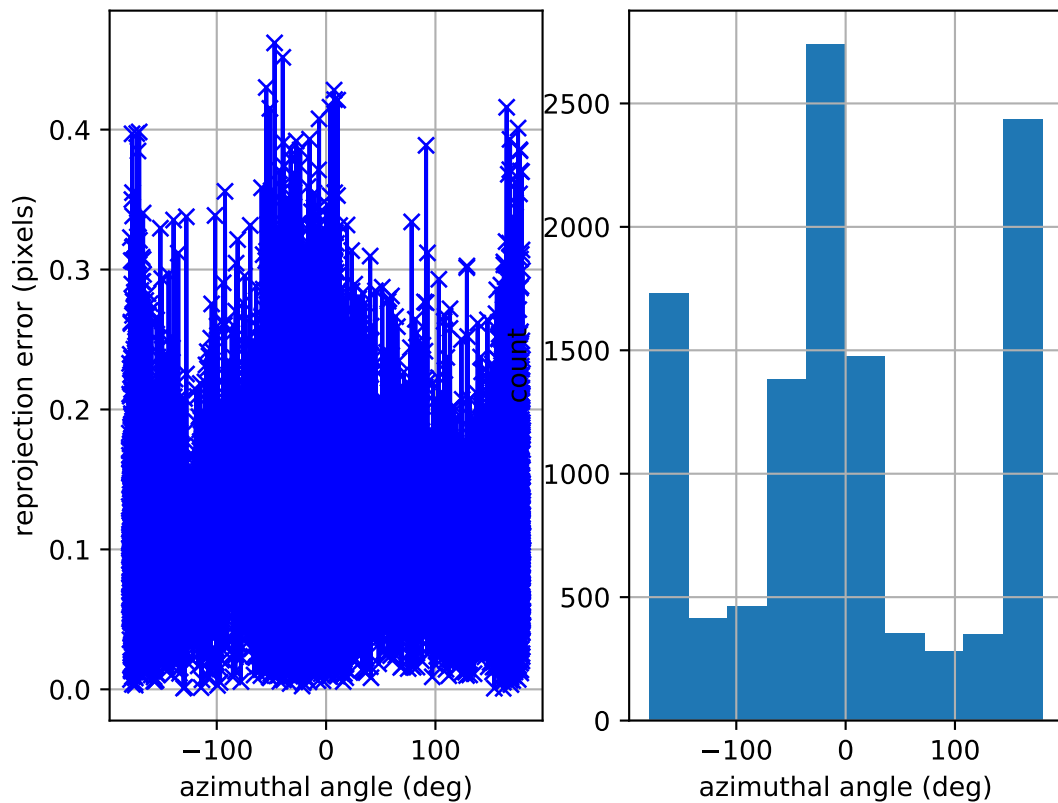cam0: azimuthal error
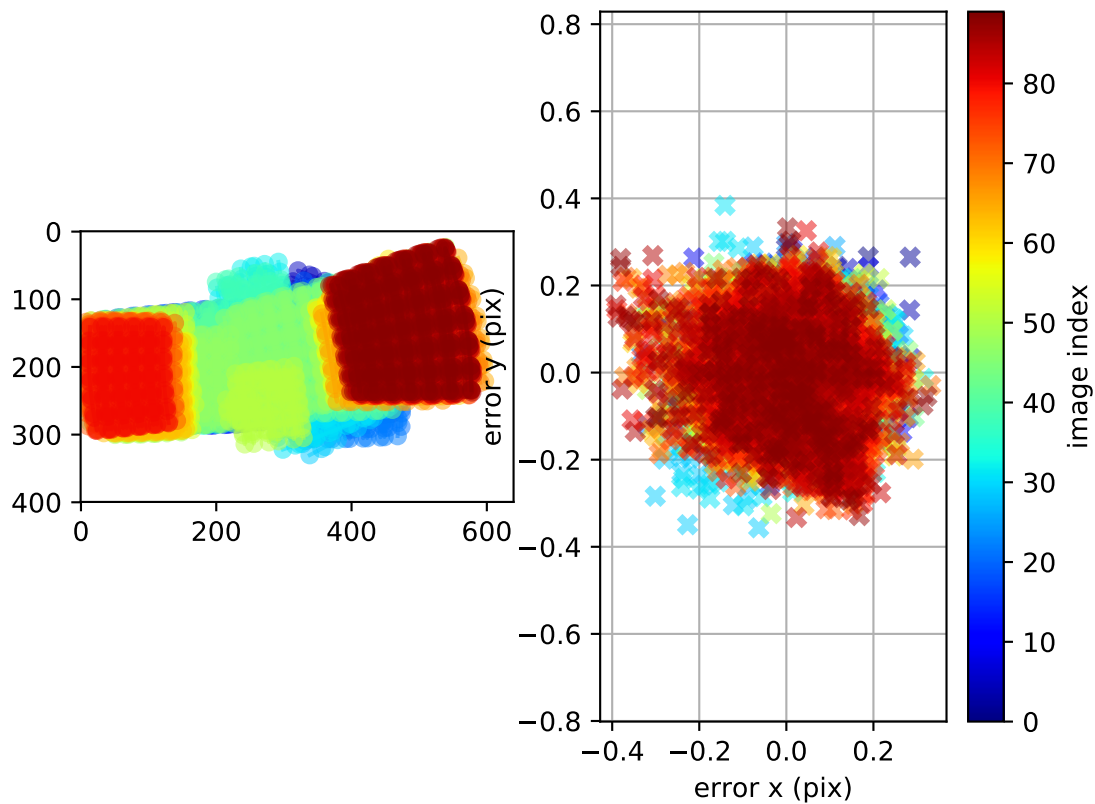
cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners