Calibration results
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Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedOmniCameraGeometry'>
distortion: [-0.11604467 0.99060823 -0.00355041 -0.00245977] +- [0.01254061 0.06815057 0.00036956 0.00030727]
projection: [1.8975984   830.7004541   831.57961722 318.43467947 203.22992977] +- [0.00739497 0.15852858
0.15856735 0.27893772 0.16747936]
reprojection error: [-0.000010, -0.000030] +- [0.092958, 0.088022]

cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DistortedOmniCameraGeometry'>
distortion: [-0.09993415 1.07248929 -0.0050298 -0.00353097] +- [0.01248385 0.06760352 0.00038653 0.00045953]
projection: [1.93776399 842.21024213 842.62127505 318.50383506 202.72239737] +- [0.00709989 0.16390335
0.16402982 0.27216172 0.17951131]
reprojection error: [-0.000002, -0.000028] +- [0.087217, 0.088679]

baseline T_1_0:
q: [-0.00248918 -0.00567402 -0.01239682 0.99990396] +- [0.00082561 0.00159461 0.00011408]
t: [-0.08058153 -0.00006604 0.00003606] +- [0.0002802   0.00022886 0.0005729]

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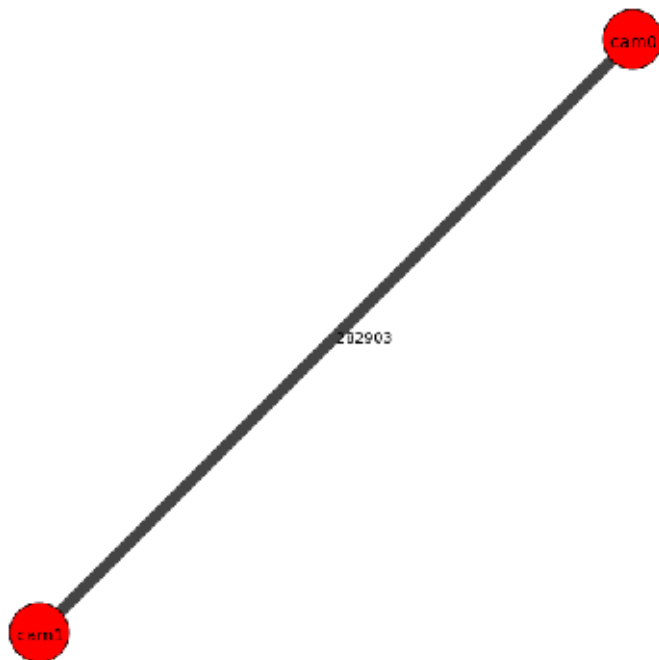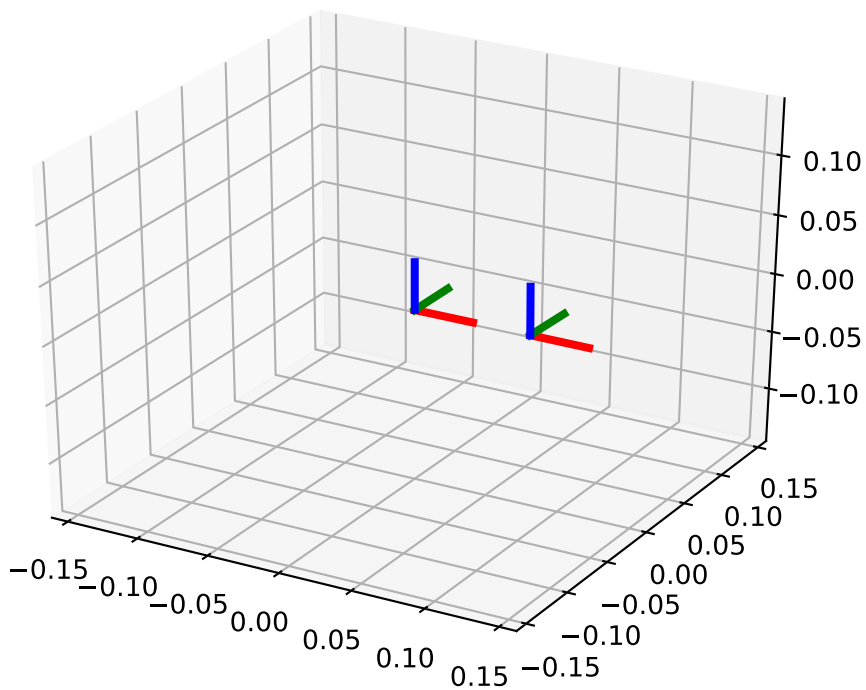====================

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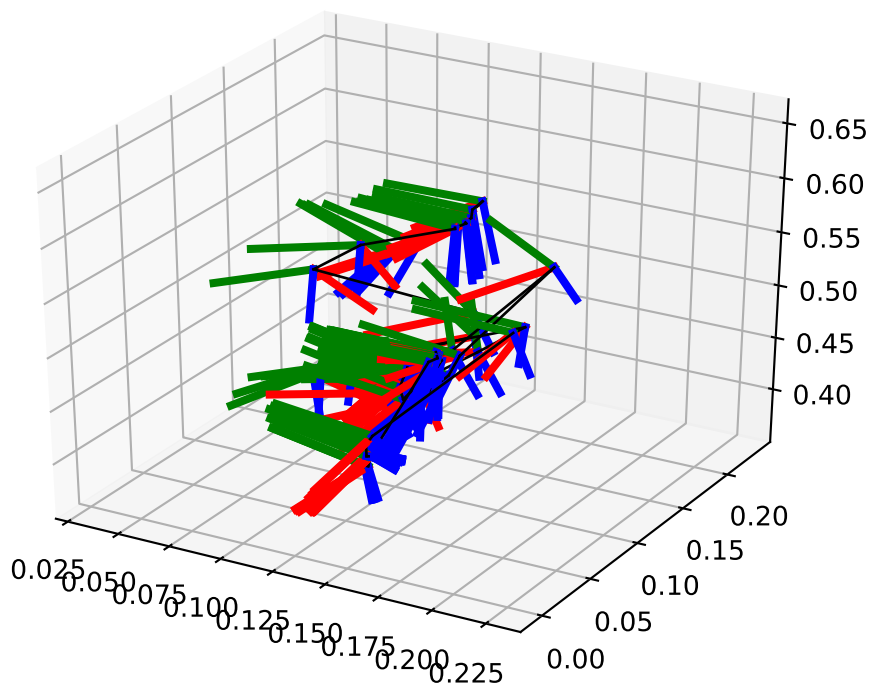Size: 0.0312 [m]
Spacing 0.00959999976 [m]

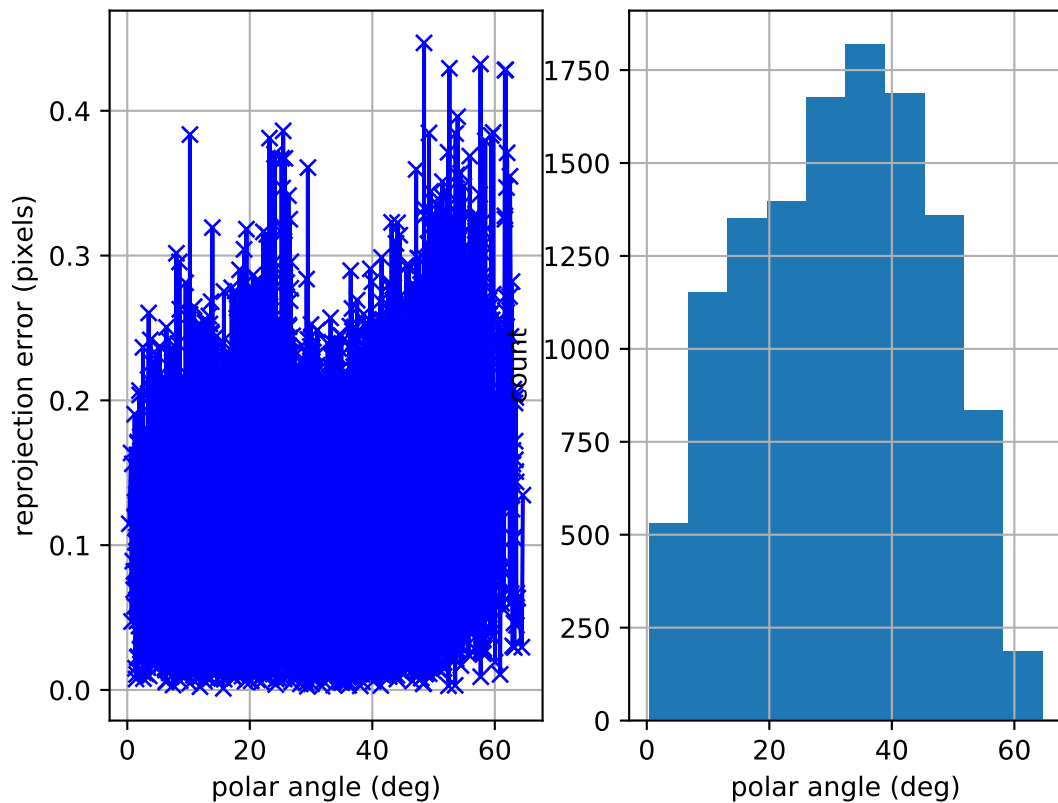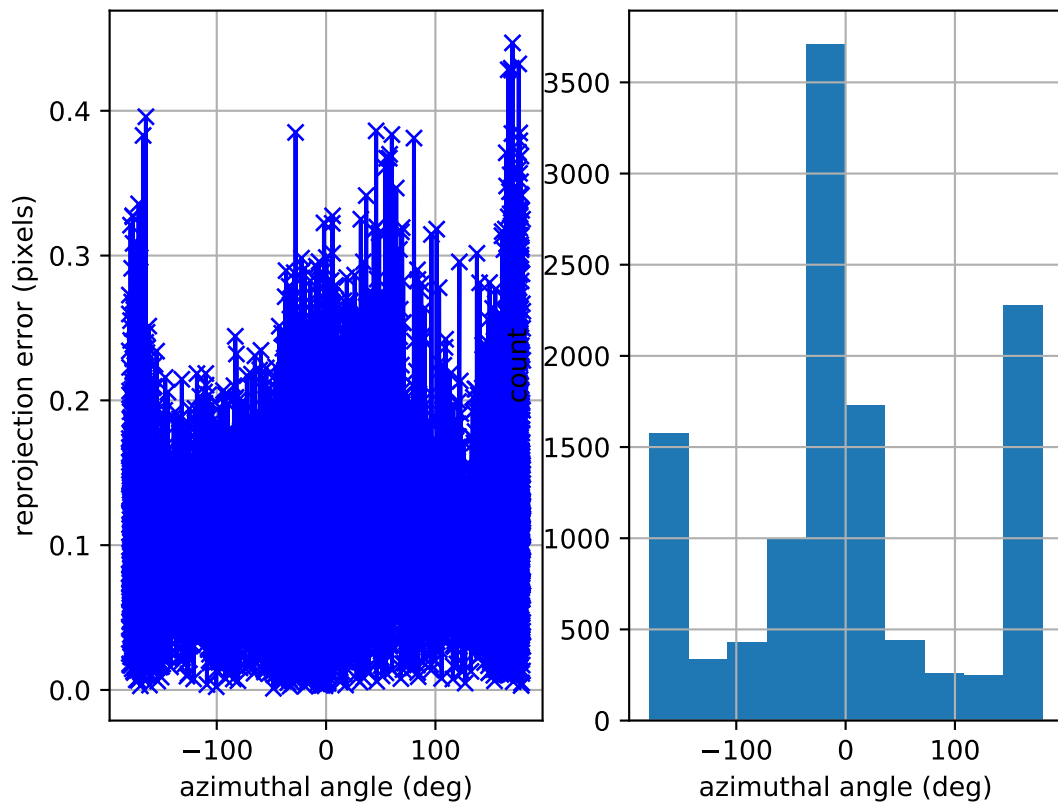# Inter-camera observations graph (edge weight=#mutual obs.)
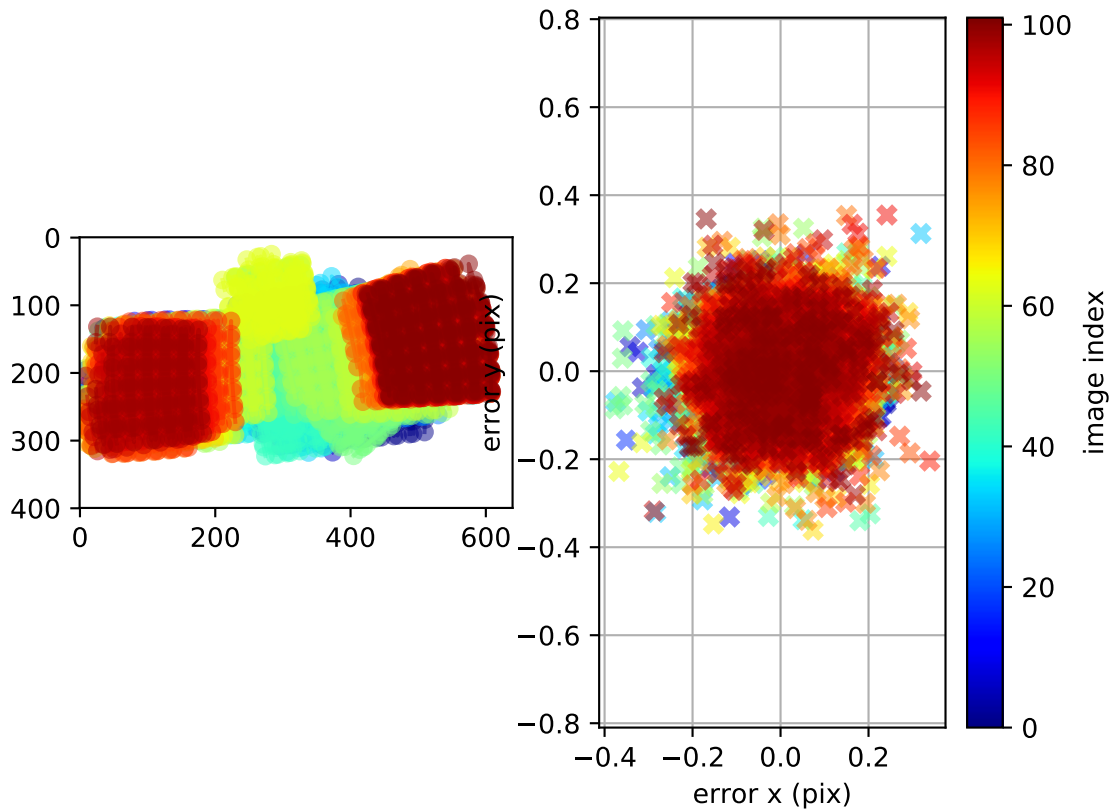
camera system

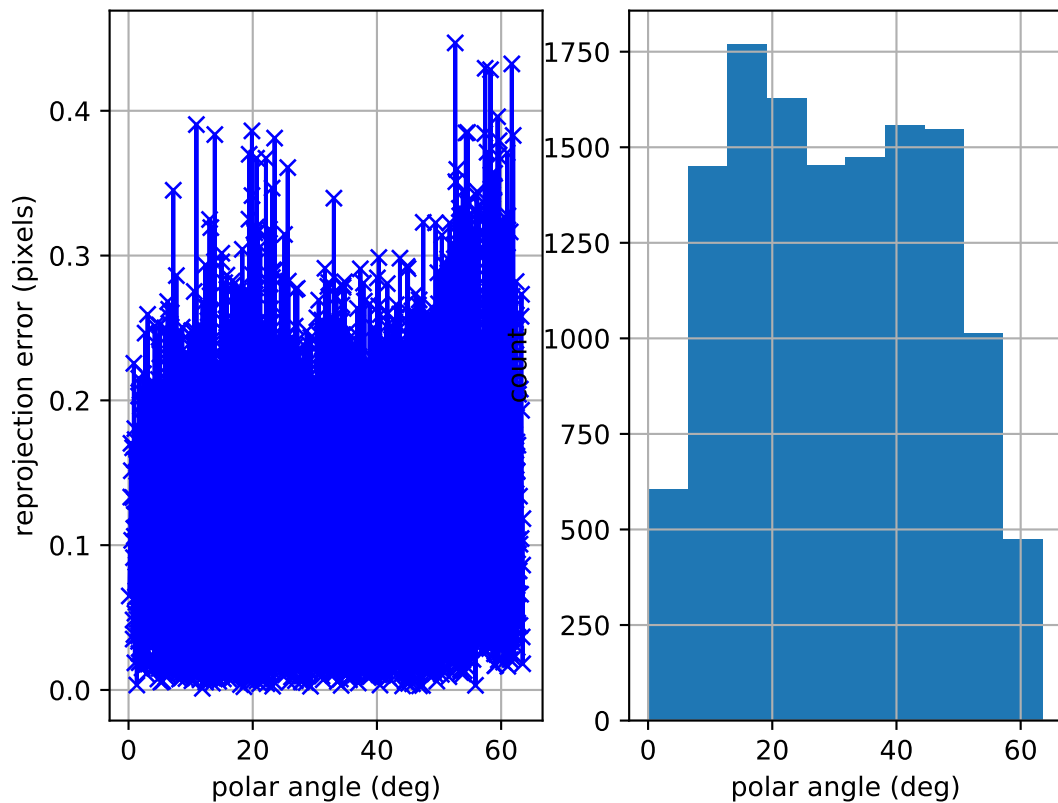cam0: estimated poses

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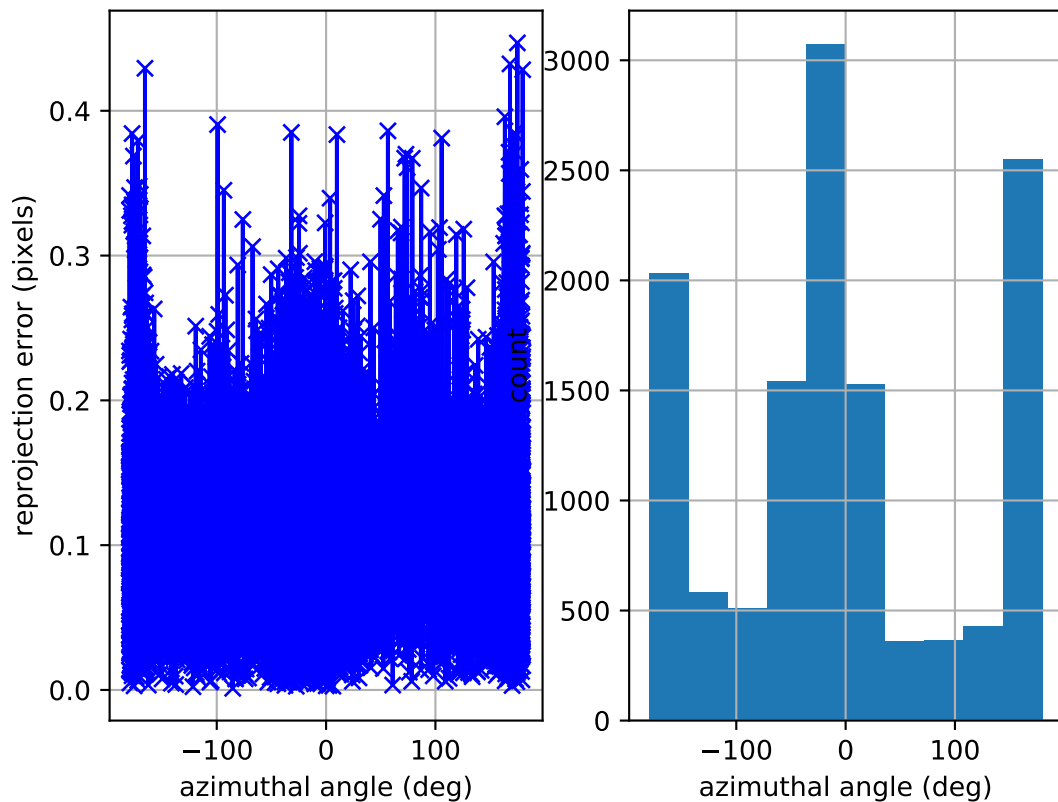
cam0: azimuthal error
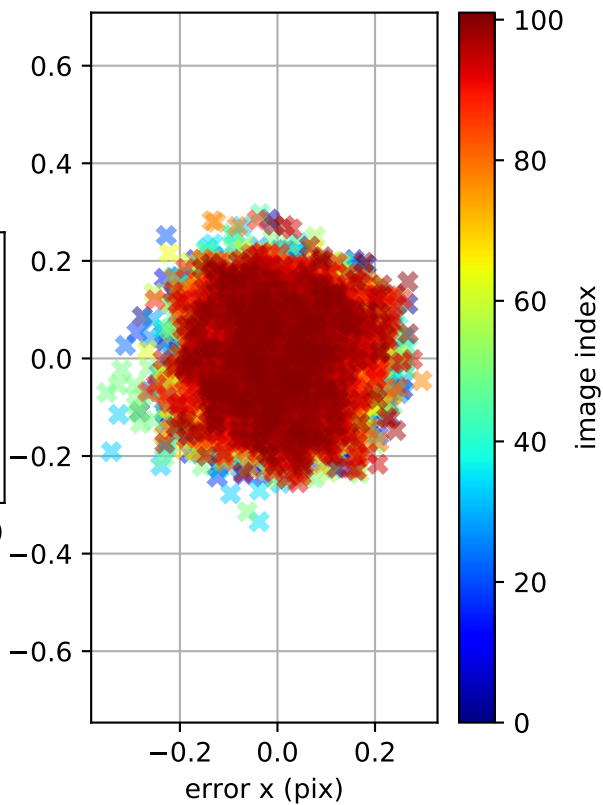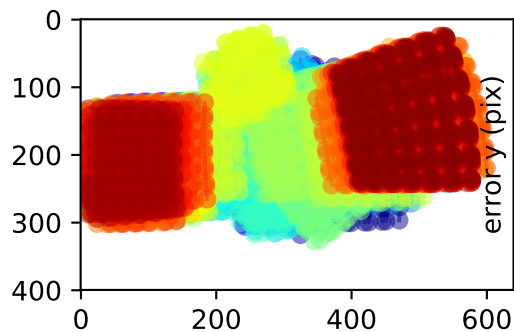
cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners