Calibration results
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Camera-system parameters:
cam0 (/cam0/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DoubleSphereCameraGeometry'>
distortion: [] +- []
projection: [-0.27856548   0.56073227 208.71565183 209.26946491 316.28921713
200.84278624] +- [0.00429009 0.0016257   0.02160575 0.02113835 0.2876228   0.27309934]
reprojection error: [0.000000, 0.000000] +- [0.123744, 0.115924]

cam1 (/cam1/image_raw):
type: <class 'aslam_cv.libaslam_cv_python.DoubleSphereCameraGeometry'>
distortion: [] +- []
projection: [-0.28957071   0.55486956 205.35387551 205.87112526 315.97830018
199.96970962] +- [0.00443743 0.00153443 0.02288795 0.02218324 0.30931352 0.27474741]
reprojection error: [-0.000000, 0.000000] +- [0.129500, 0.113754]

baseline T_1_0:
q: [-0.00222643 -0.00630865 -0.01218391 0.99990339] +- [0.000718   0.00110802 0.00014457]
t: [-0.08041777 0.00003535 0.00012768] +- [0.00013097 0.0001135   0.00036584]

Target configuration
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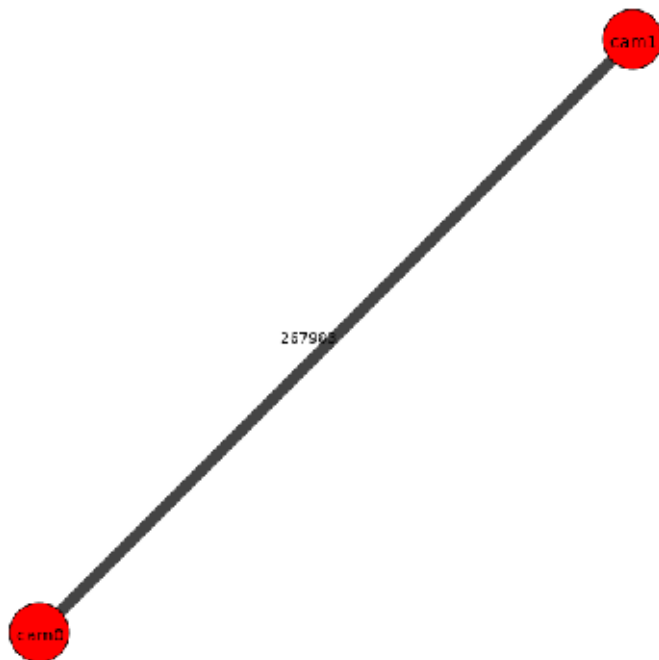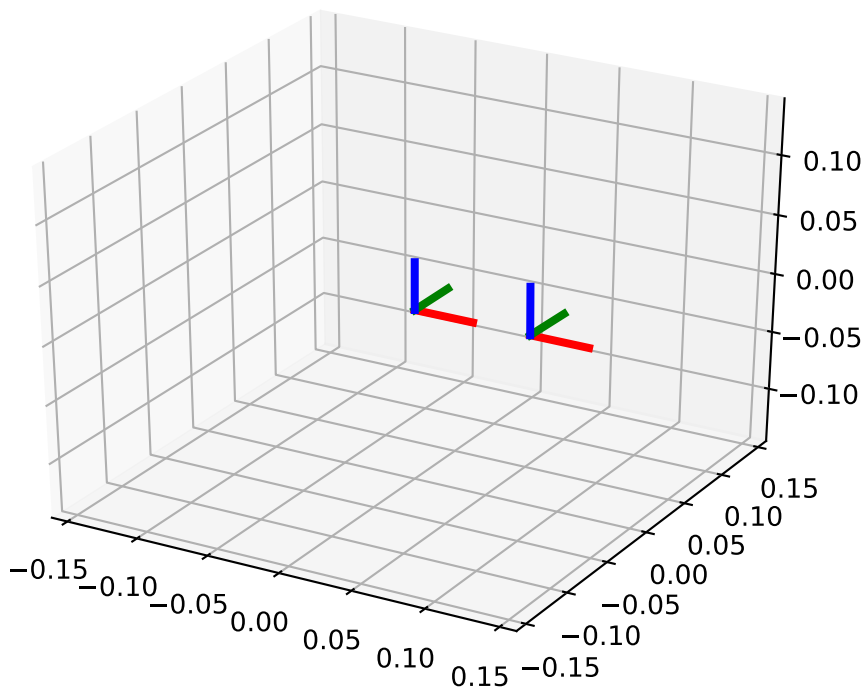
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0312 [m]
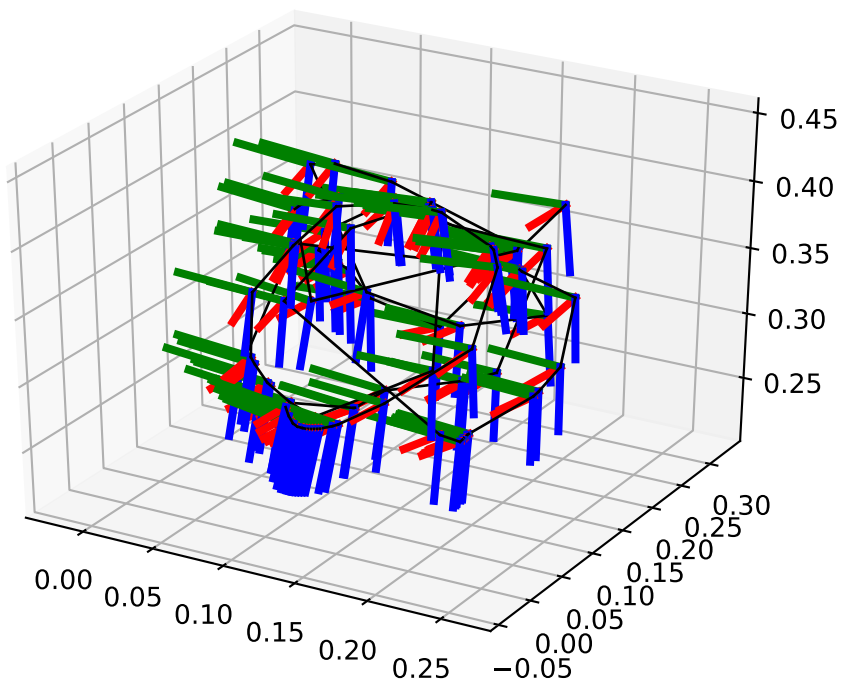Spacing 0.00959999976 [m]
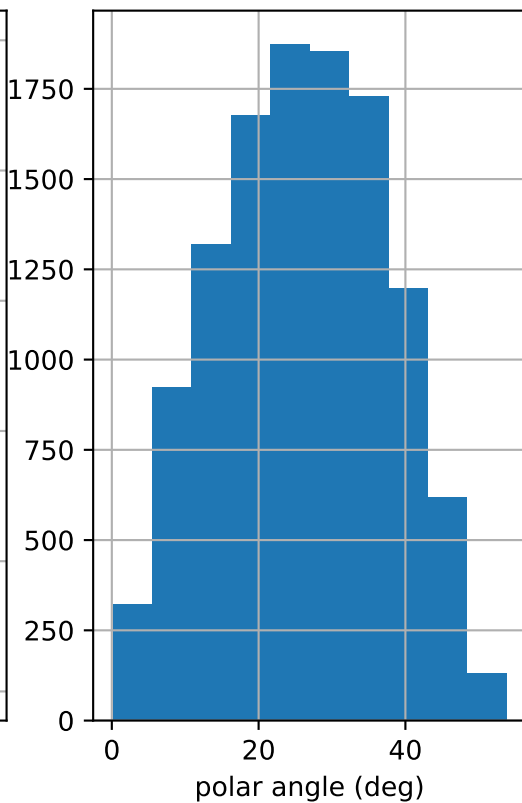
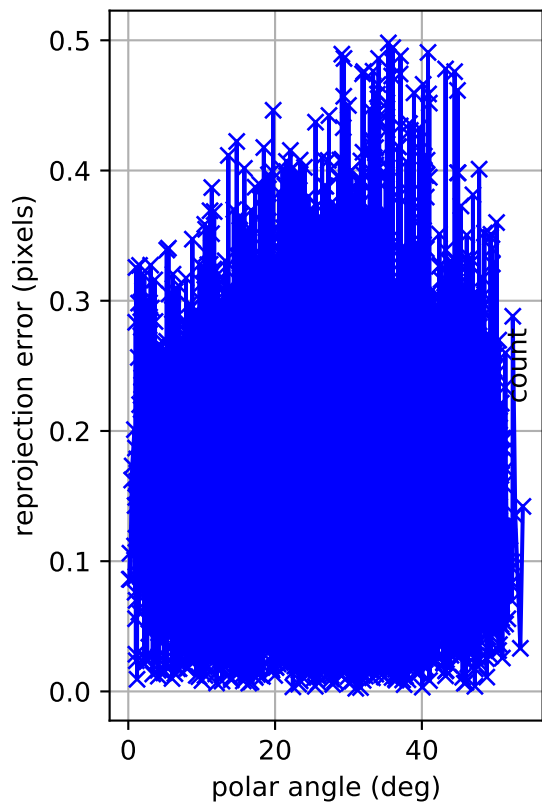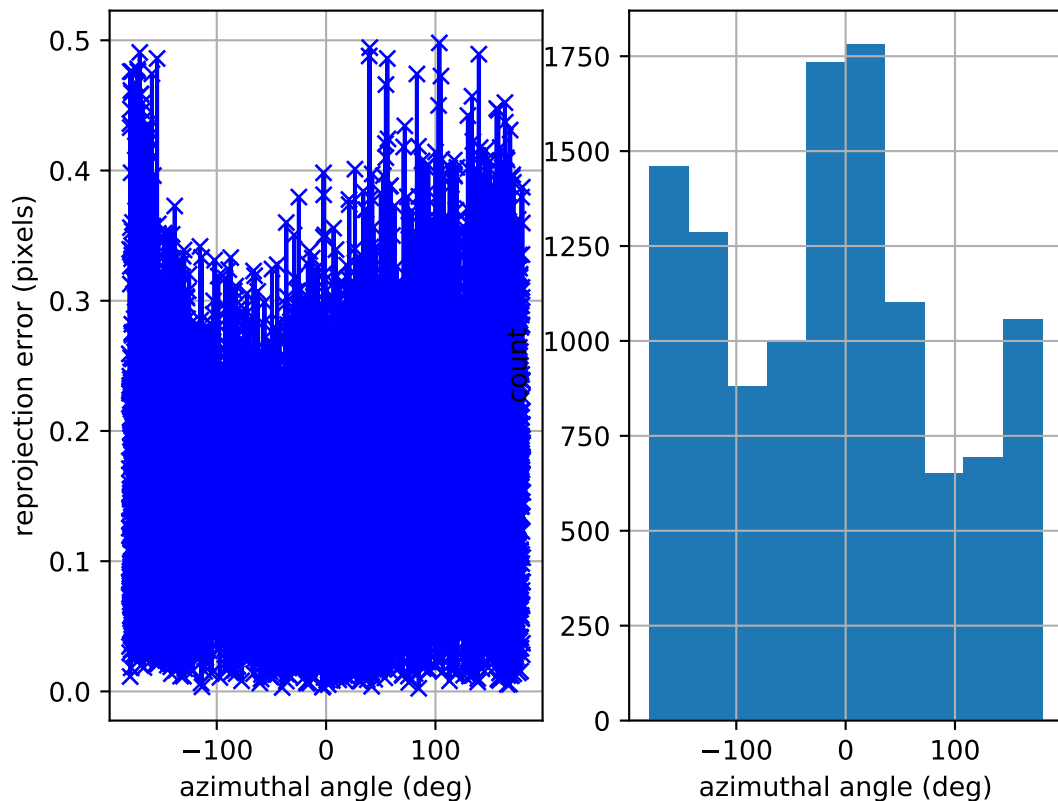# Inter-camera observations graph (edge weight=#mutual obs.)
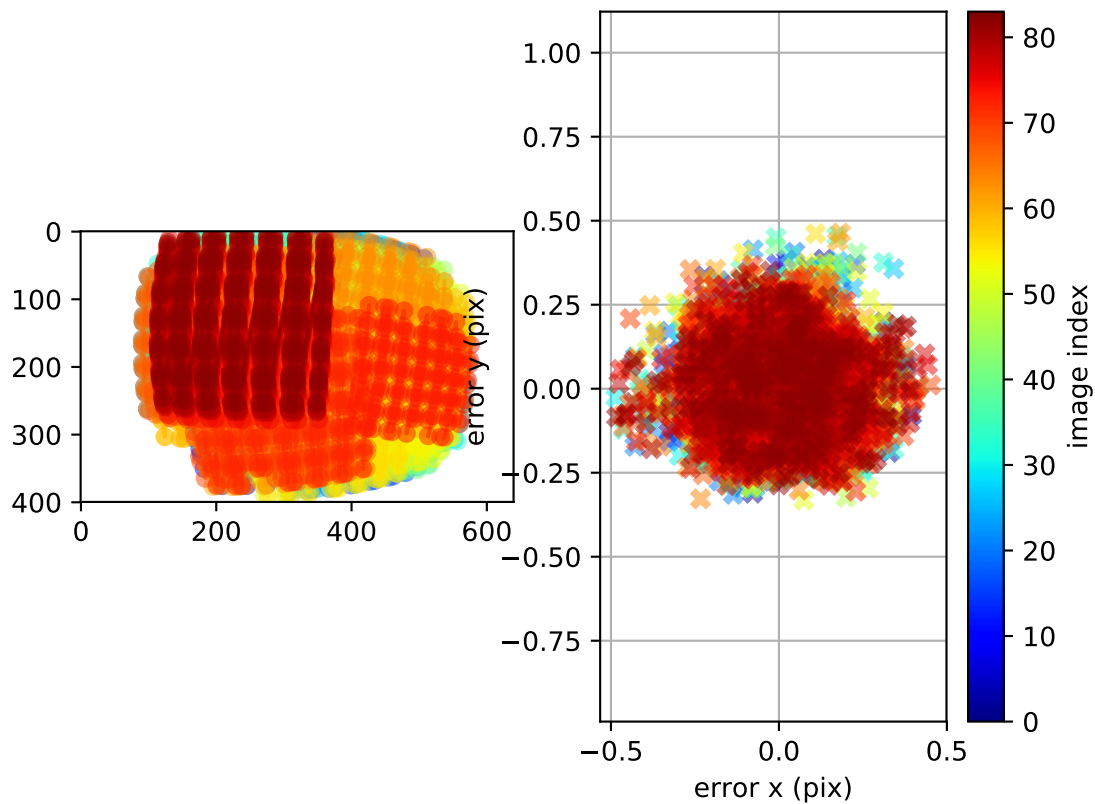
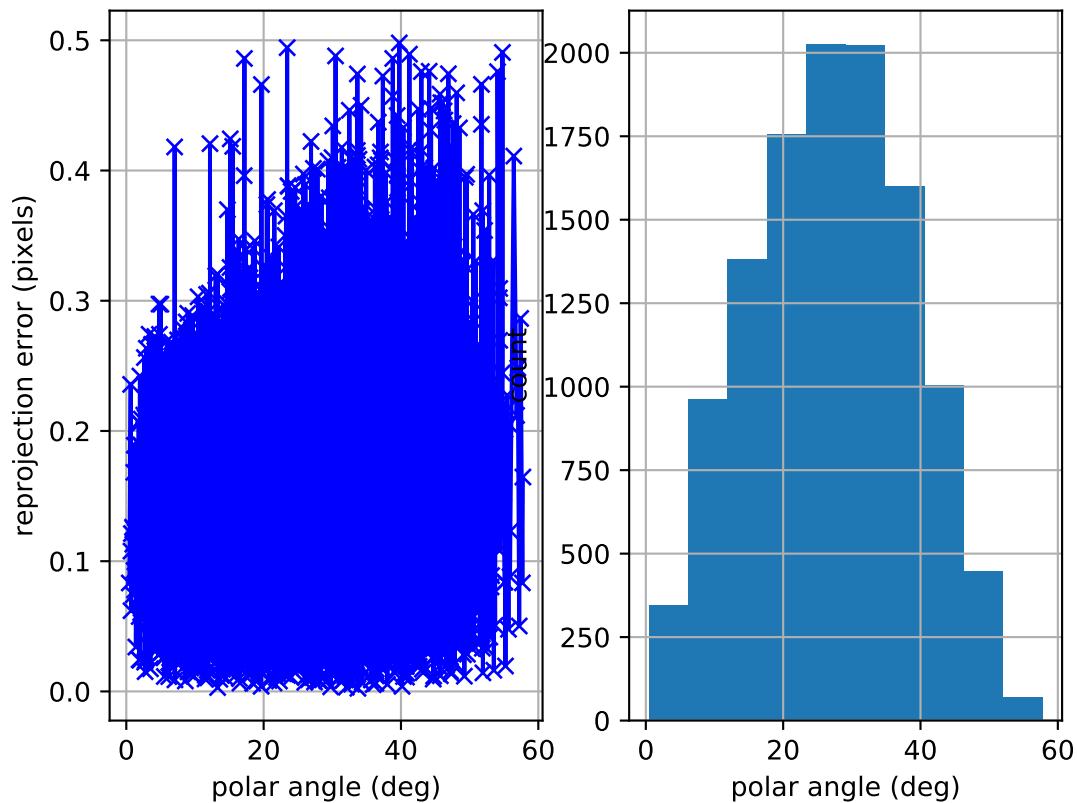camera system

cam0: estimated poses

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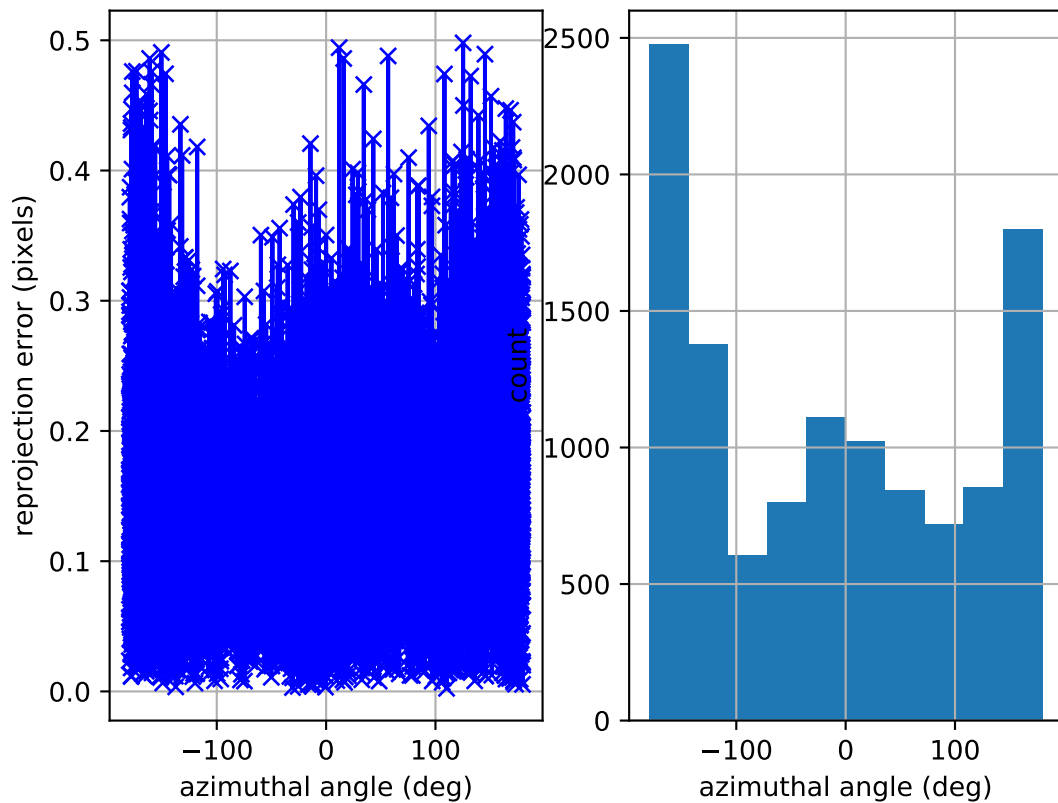
cam0: azimuthal error
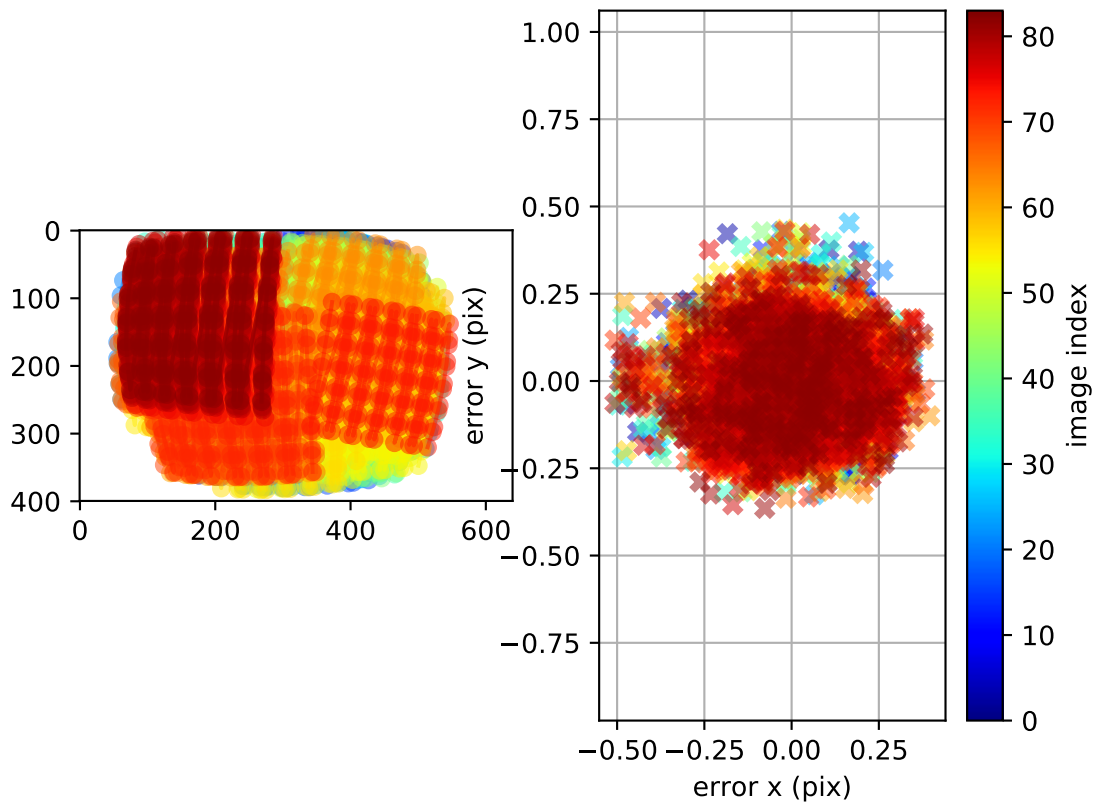
cam0: reprojection errors

cam1: polar error

cam1: azimuthal error

cam1: reprojection errors

Location of removed outlier corners