WHAT IS CLAIMED IS:

1. A tool assembly comprising:

an elongated body, the elongated body defines a local longitudinal direction, a latitudinal direction, and a transverse direction;

a first camera fixed to the elongated body at a first location and having a first orientation relative to the elongated body;

a second camera fixed to the elongated body at a second location spaced a known spatial distance from the first location and having a second orientation relative to the elongated body, the first orientation defines an angle with the second orientation relative to a plane defined by the latitudinal direction and the transverse direction greater than zero and less than 360 degrees; and

a controller in operative communication with the first camera and the second camera, the controller being configured to:

receive data indicative of one or more images of a reference feature from the first camera;

determine data indicative of a first spatial position of the first camera based at least in part on the received data indicative of the one or more images of the reference feature; and

determine data indicative of a second spatial position of the second camera based on a known spatial relationship between the first location and the second location; and

receive data indicative of one or more images of a target feature using the second camera,

wherein the first camera and the second camera being simultaneously in view of the reference feature and the target feature, respectively, and the target feature not being in view of the first camera.

2. The tool assembly of claim 1, wherein the first spatial position comprises a first position and a first orientation of the first camera within an apparatus, and wherein the second spatial position comprises a second position and a second orientation of the second camera within the apparatus.

3. The tool assembly of claim 1, wherein the controller is further configured to:

determine data indicative of one or more dimensions of the target feature based at least in part on the received data indicative of the one or more images of the target feature.

4. The tool assembly of claim 3, wherein the controller is further configured to:

generate a three-dimensional representation of the target feature using the determined data indicative of the one or more dimensions of the target feature.

5. The tool assembly of claim 1, wherein the reference feature is located on a first component, and wherein the target feature is located on a second component.

6. The tool assembly of claim 1, wherein the data including at least a distance relative to the reference feature and a vector from the reference feature to the first camera.

7. The tool assembly of claim 1, wherein each of the first camera and the second camera further comprise one or more sensors, wherein the one or more sensors provide data to the controller.

8. The tool assembly of claim 1, the tool assembly further comprising:

a third camera fixed to the elongated body at a third location spaced from the first location and the second location, wherein the third camera is positioned in view of an auxiliary feature.

9. The tool assembly of claim 8, wherein the controller is further configured to:

determine a third spatial position of the third camera based on the first spatial position, the second spatial position, or both;

receive data indicative of one or more images of the auxiliary feature from the third camera;

determine data indicative of dimensions of the auxiliary feature based at least in part on the received data indicative of one or more images of the auxiliary feature; and

generate a three-dimensional representation of the auxiliary feature based at least in part on the determined data indicative of the dimensions of the auxiliary feature.

10. A method for inspecting using a tool assembly, the tool assembly comprising an elongated body, a first camera fixed to the elongated body at a first location, a second camera fixed to the elongated body at a second location spaced a known spatial distance from the first location, the elongated body defining a local longitudinal, a latitudinal direction, and a transverse direction, the first camera having a first orientation relative to the elongated body, the second camera having a second orientation relative to the elongated body, and the first orientation defining an angle with the second orientation relative to a plane defined by the latitudinal direction and the transverse direction greater than zero and less than 360 degrees, the method comprising:

positioning the elongated body such that the first camera is in view of a reference feature;

receiving data indicative of one or more images of the reference feature from the first camera;

determining data indicative of a first spatial position of the first camera based at least in part on the received data indicative of the one or more images of the reference feature;

determining data indicative of a second spatial position of the second camera based on a known spatial relationship between the first location and the second location; and

receiving data indicative of one or more images of a target feature using the second camera,

wherein the first camera and the second camera being simultaneously in view of the reference feature and the target feature, respectively, and the target feature not being in view of the first camera.

11. The method of claim 10, the method further comprising:

determining data indicative of one or more dimensions of the target feature.

12. The method of claim 11, the method further comprising:

generating a three-dimensional representation of the target feature based at least in part on the determined data indicative of the one or more dimensions of the target feature.

13. The method of claim 12, wherein generating the three-dimensional representation of the target feature further comprises:

generating a point cloud.

14. The method of claim 10, wherein positioning the elongated body such that the first camera is in view of the reference feature comprises:

inserting the elongated body into a gas turbine engine having the reference feature.

15. The method of claim 14, wherein the reference feature is located on a first component, and wherein the target feature is located on a second component.

16. The method of claim 14, wherein the first spatial position comprises a first position and a first orientation of the first camera within the gas turbine engine, and wherein the second spatial position comprises a second position and a second orientation of the second camera within the gas turbine engine.

17. The method of claim 10, wherein the tool assembly further comprises a third camera fixed to the elongated body at a third location spaced from the first location, the second location, or both, wherein the third camera is positioned in view of an auxiliary feature.

18. The method of claim 17, wherein the method further comprises:

determining a third spatial position of the third camera based at least in part on the first spatial position or the second spatial position;

receiving data indicative of one or more images of the auxiliary feature using the third camera;

determining data indicative of one or more dimensions of the auxiliary feature based at least in part on the received data indicative of one or more images of the auxiliary feature; and

generating a three-dimensional representation of the auxiliary feature based at least on the determined data indicative of the one or more dimensions of the auxiliary feature.