Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.448904022876, median 0.318087524674, std: 0.414112834308
Gyroscope error (imu0):   mean 1.34299294479, median 1.1973707844, std: 0.998970030357
Accelerometer error (imu0):   mean 4.70153549989, median 3.54687350315, std: 3.55084690564

Residuals

Reprojection error (cam0) [px]:   mean 0.448904022876, median 0.318087524674, std: 0.414112834308
Gyroscope error (imu0) [rad/s]:   mean 0.0949639418346, median 0.0846669001246, std: 0.0706378482660
Accelerometer error (imu0) [m/s^2]: mean 0.664897526792, median 0.501603661218, std: 0.50216558518

Transformation (cam0):

T_ci: (imu0 to cam0):
[[0.00199812 0.99977399 -0.02116558 0.04081412]
 [-0.99975857 0.00246034 0.02183479 -0.02259298]
 [0.02188193 0.02111684 0.99953752 0.02261085]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[0.00199812 -0.99975857 0.02188193 -0.02316385]
 [0.99977399 0.00246034 0.02111684 -0.04122677]
 [-0.02116558 0.02183479 0.99953752 -0.02124322]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
0.00067561065344462393

Gravity vector in target coords: [m/s^2]
[-0.08225096 8.29435031 -5.23119591]

Calibration configuration

 Camera model: pinhole
 Focal length: [461.7947310011125, 460.24678913375317]
 Principal point: [359.8335340985467, 233.72090134082393]
 Distortion model: equidistant
 Distortion coefficients: [0.0023809655849981798, 0.000379091478428235, 0.0018750627605088345, 0.0
 Type: aprilgrid
 Tags:
  Rows: 6
  Cols: 6
  Size: 0.02 [m]
  Spacing 0.006 [m]

IMU configuration
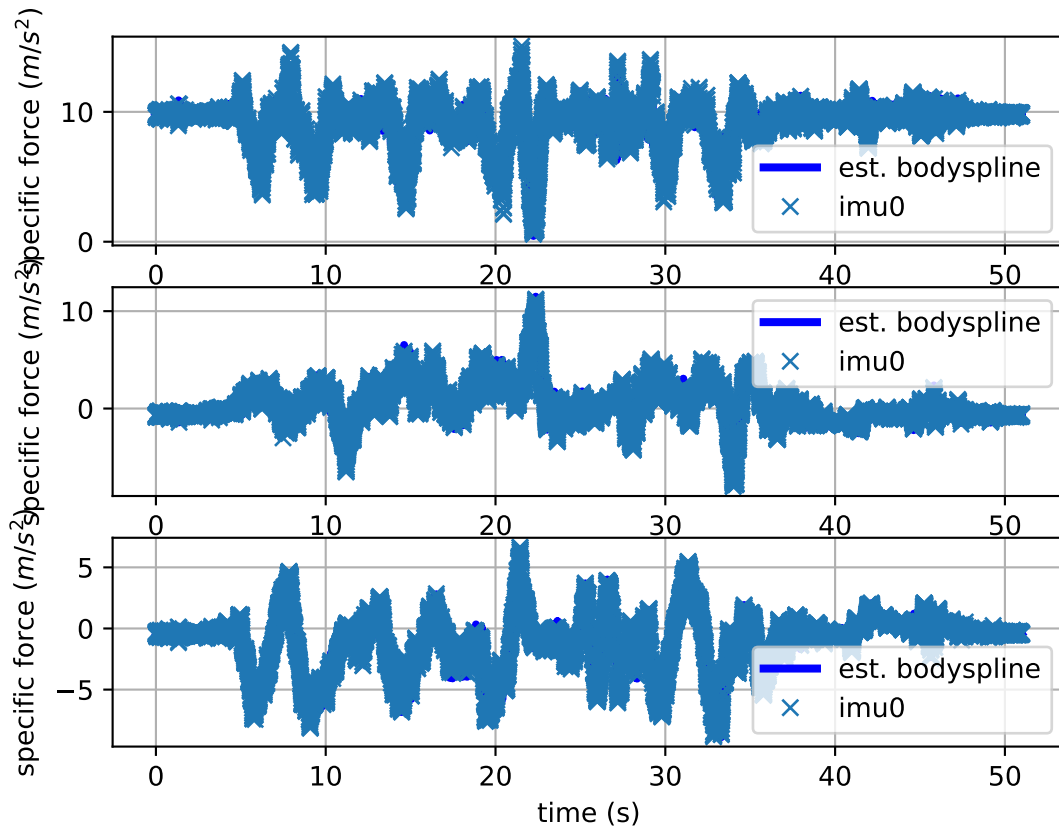=================

IMU0:

 Model: calibrated
 Update rate: 200.0
 Accelerometer:
  Noise density: 0.01
  Noise density (discrete): 0.141421356237
  Random walk: 0.0002
 Gyroscope:
  Noise density: 0.005
  Noise density (discrete): 0.0707106781187
  Random walk: 4e-06
 T_i_b
  [[1. 0. 0. 0.]
   [0. 1. 0. 0.]
   [0. 0. 1. 0.]
   [0. 0. 0. 1.]]
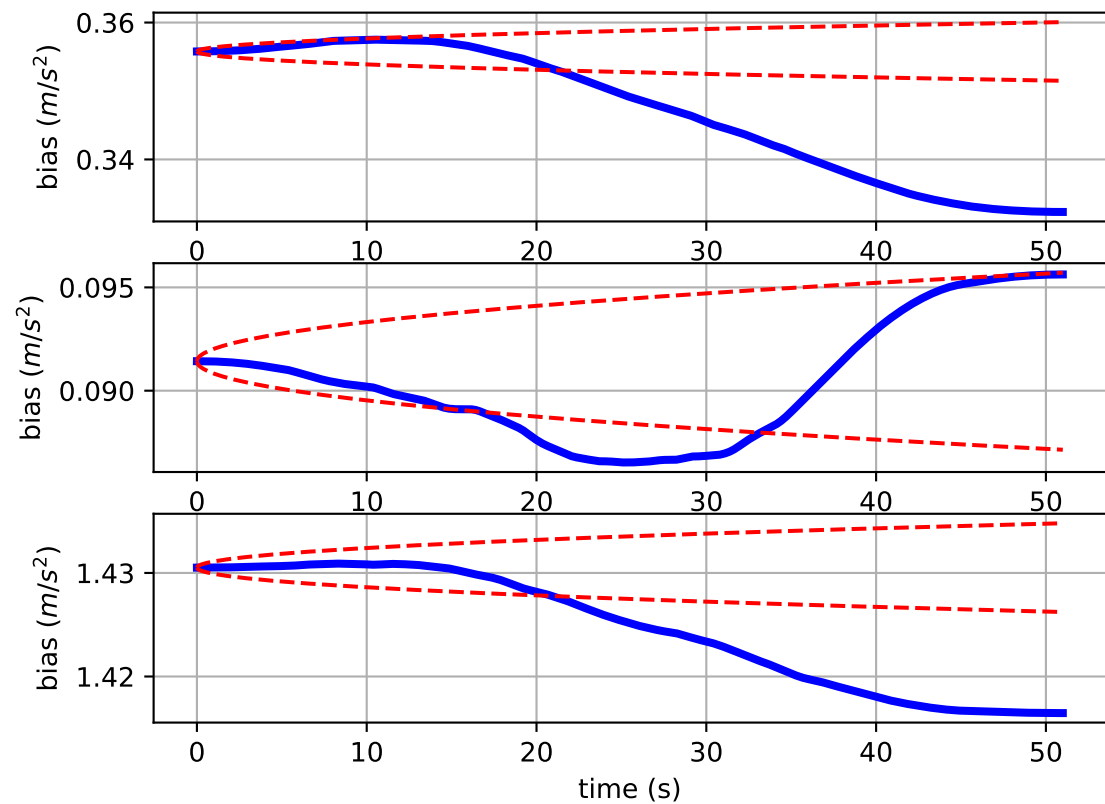 time offset with respect to IMU0: 0.0 [s]

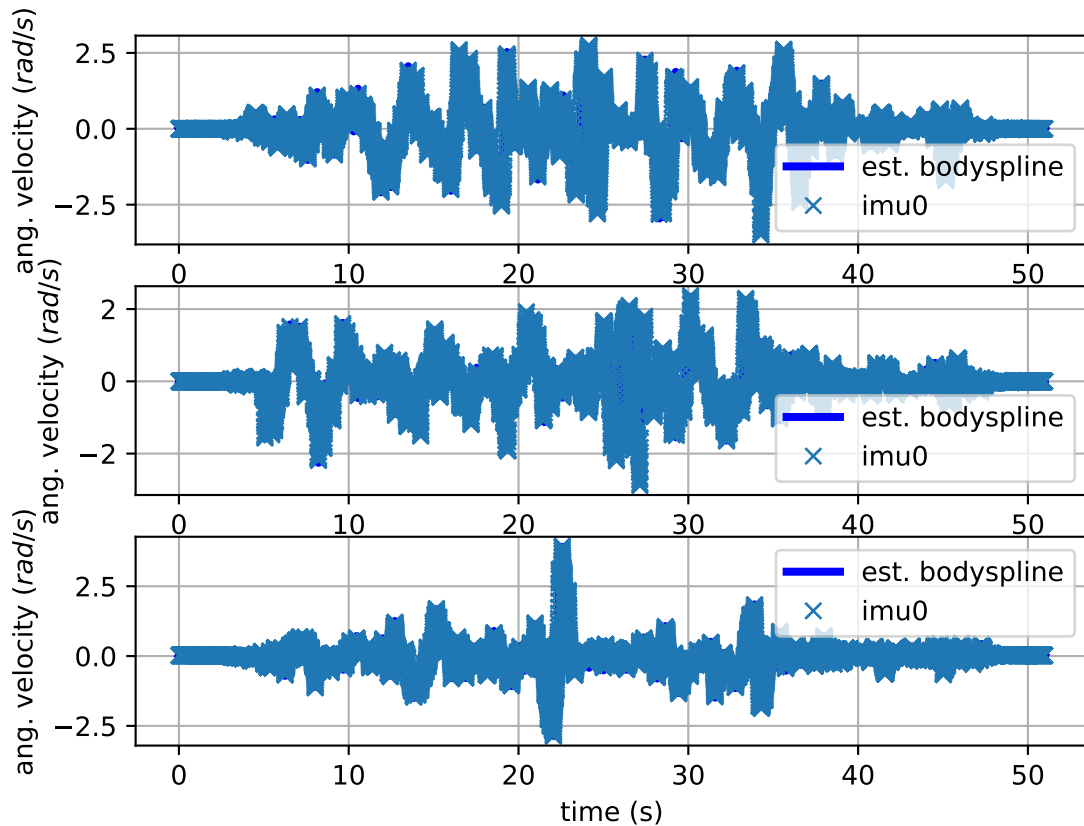Comparison of predicted and measured specific force (imu0 frame)
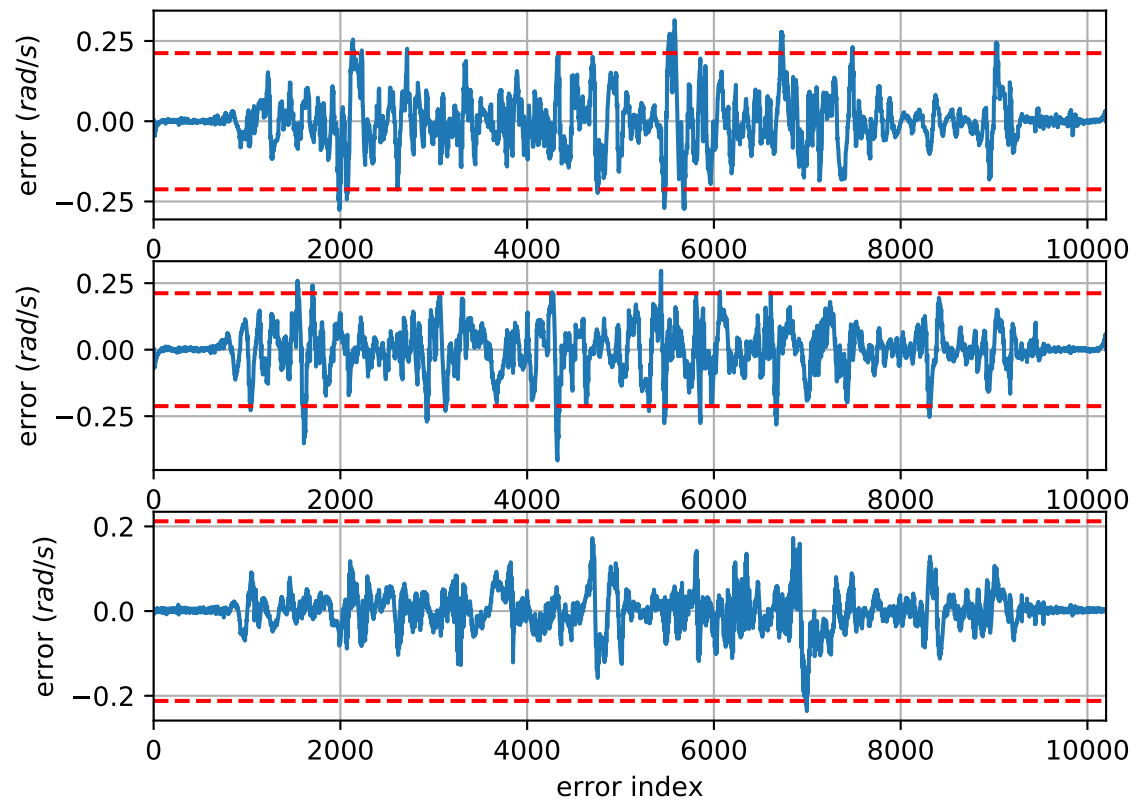
imu0: acceleration error
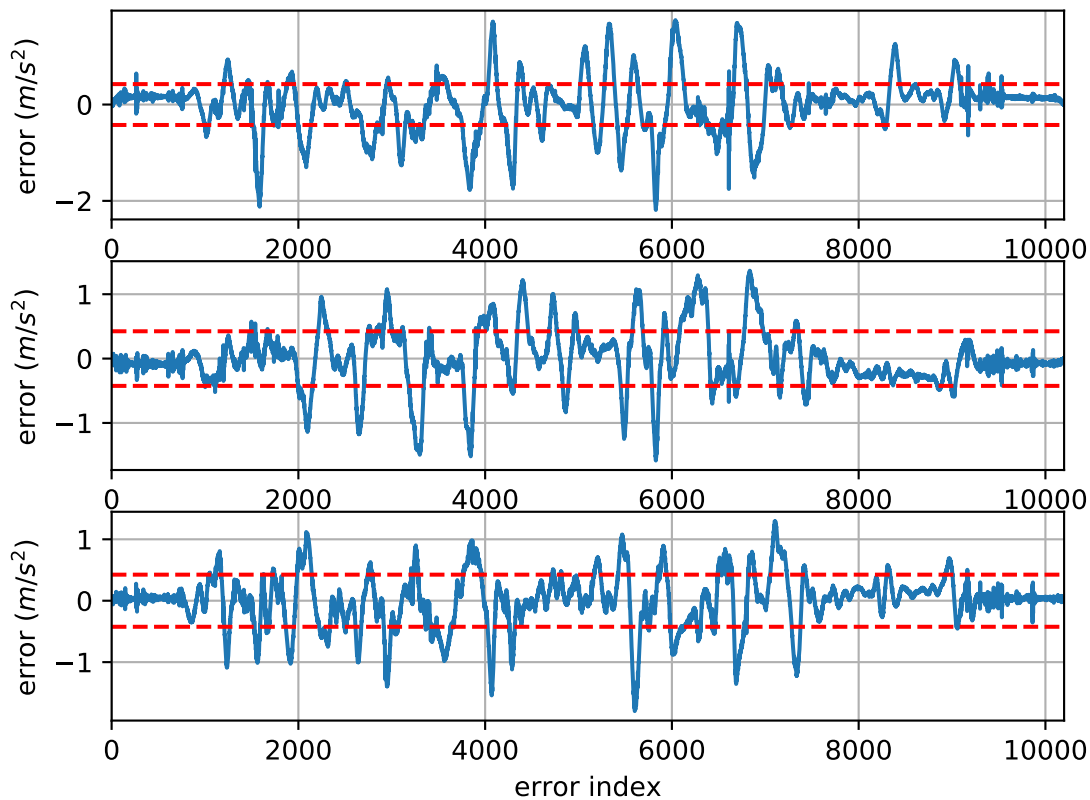
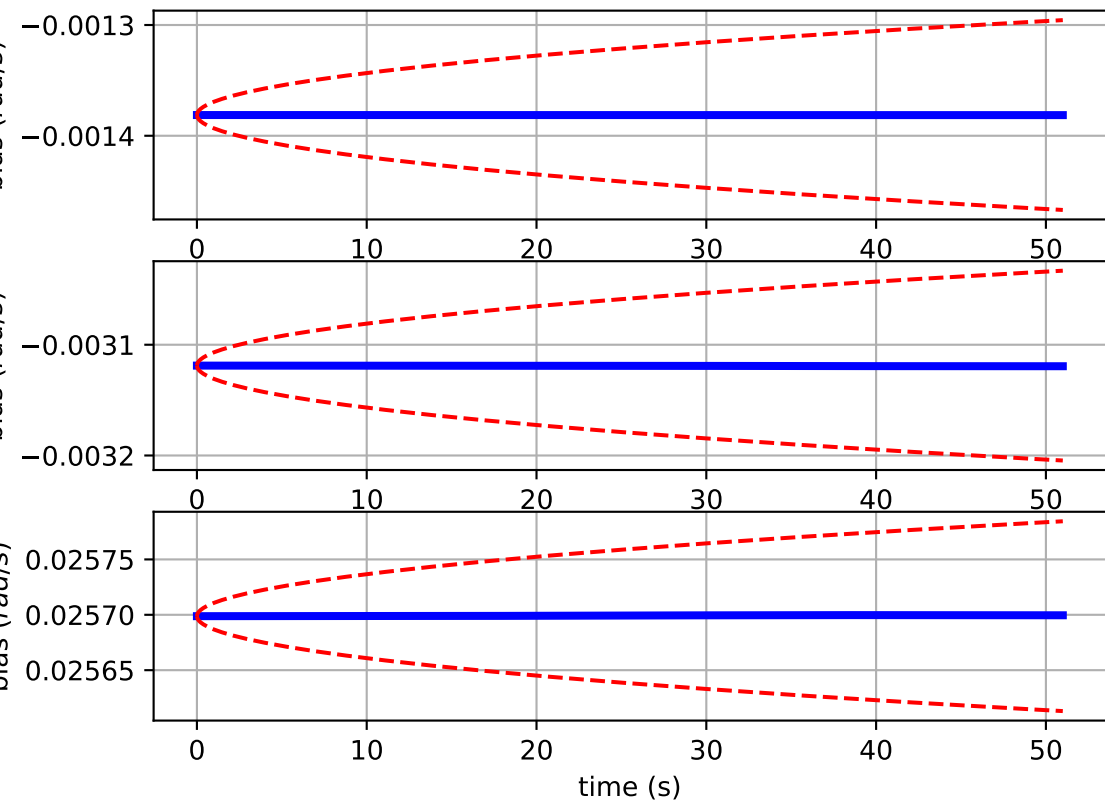imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors