Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.71885367805, median 0.342136614898, std: 0.951655452543
Gyroscope error (imu0):   mean 1.27608857228, median 0.906428784095, std: 5.17229462433
Accelerometer error (imu0):   mean 1.34107060049, median 0.847963055494, std: 6.27141196865

Residuals

Reprojection error (cam0) [px]:   mean 0.71885367805, median 0.342136614898, std: 0.951655452543
Gyroscope error (imu0) [rad/s]:   mean 0.000917546514032, median 0.000651749877816, std: 0.00371903
Accelerometer error (imu0) [m/s^2]: mean 0.0218140749278, median 0.0137931065089, std: 0.1020118184

Transformation (cam0):

T_ci: (imu0 to cam0):
[[-0.99994172 -0.01040789 0.00286796 0.03899633]
 [-0.00250096 -0.03510446 -0.99938052 -0.02349503]
 [0.01050212 -0.99932945 0.03507638 -0.20709537]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[-0.99994172 -0.00250096 0.01050212 0.04111024]
 [-0.01040789 -0.03510446 -0.99932945 -0.20737541]
 [0.00286796 -0.99938052 0.03507638 -0.01632816]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
0.024336217126

Gravity vector in target coords: [m/s^2]
[-0.03065909 -9.67851708 -1.57917385]

Calibration configuration

```
-----
  Camera model: pinhole
  Focal length: [1201.6, 1201.3]
  Principal point: [1036.8, 778.7]
  Distortion model: radtan
  Distortion coefficients: [-0.0951, 0.0893, 0.0005511, 8.2603e-05]
  Type: checkerboard
  Rows
    Count: 11
    Distance: 0.03 [m]
  Cols
    Count: 8
    Distance: 0.03 [m]



IMU configuration
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IMU0:
 ----------------------------
  Model: calibrated
  Update rate: 200.0
  Accelerometer:
    Noise density: 0.0011501915187
    Noise density (discrete): 0.0162661644508
    Random walk: 3.72985406906e-05
  Gyroscope:
    Noise density: 5.08431292483e-05
    Noise density (discrete): 0.000719030429364
    Random walk: 6.50982341241e-07
  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]
```
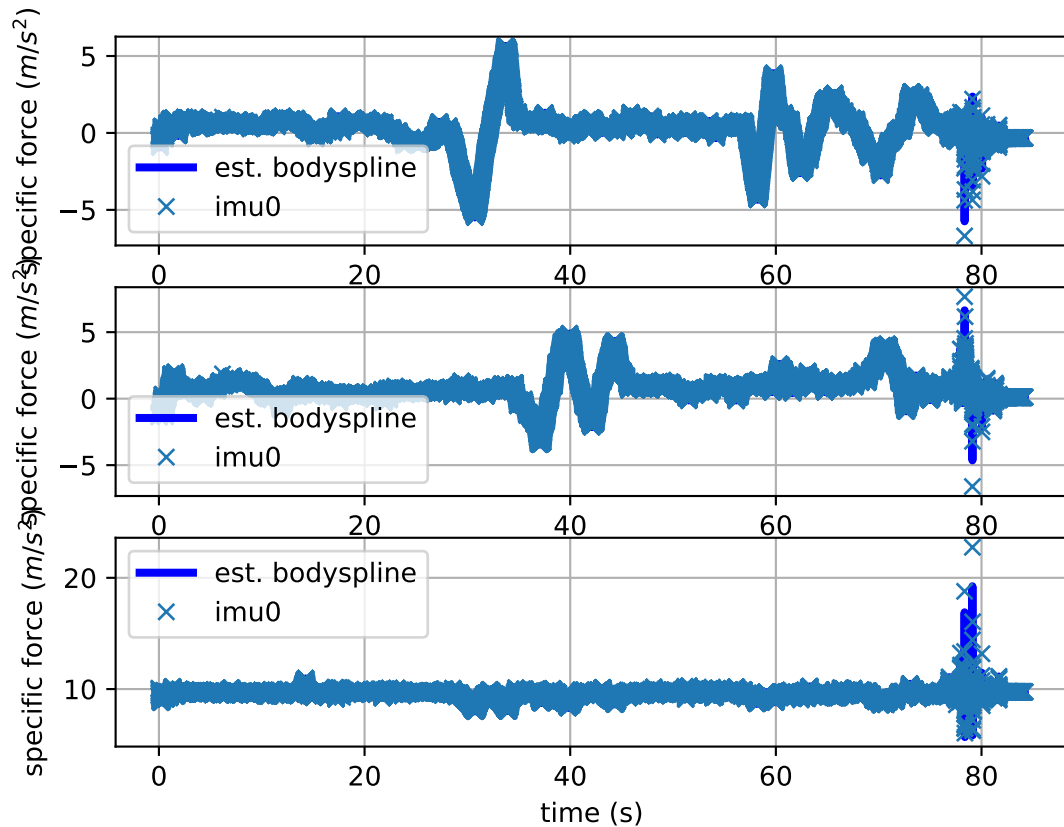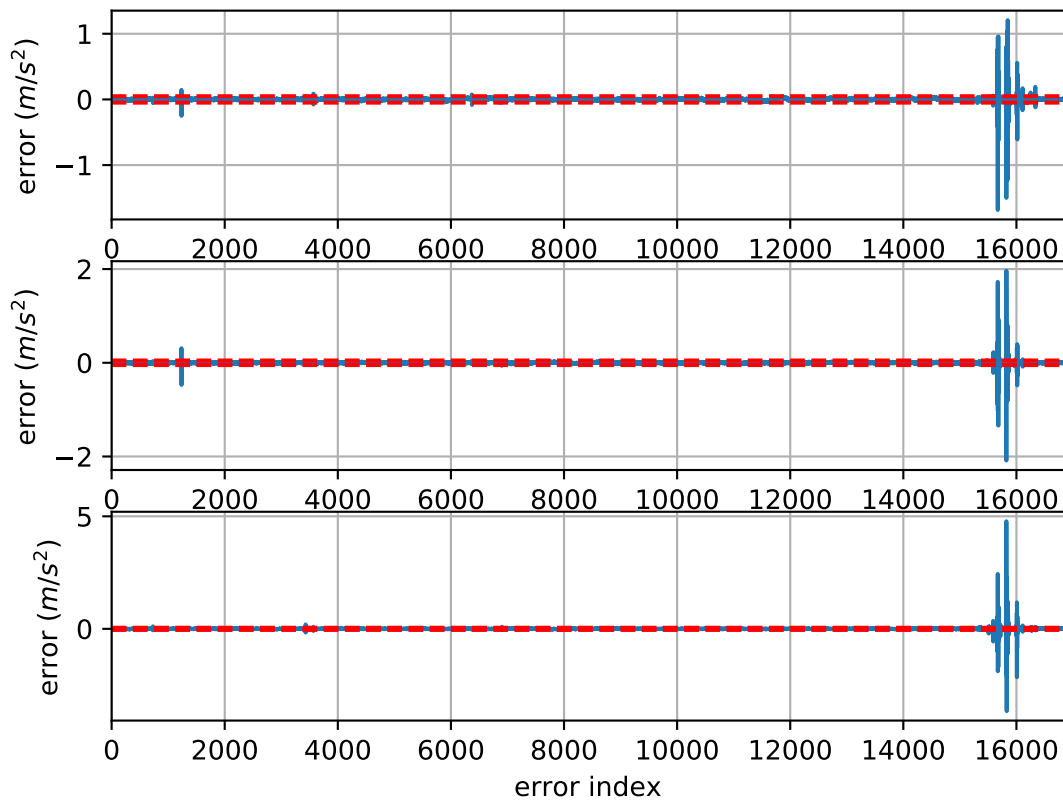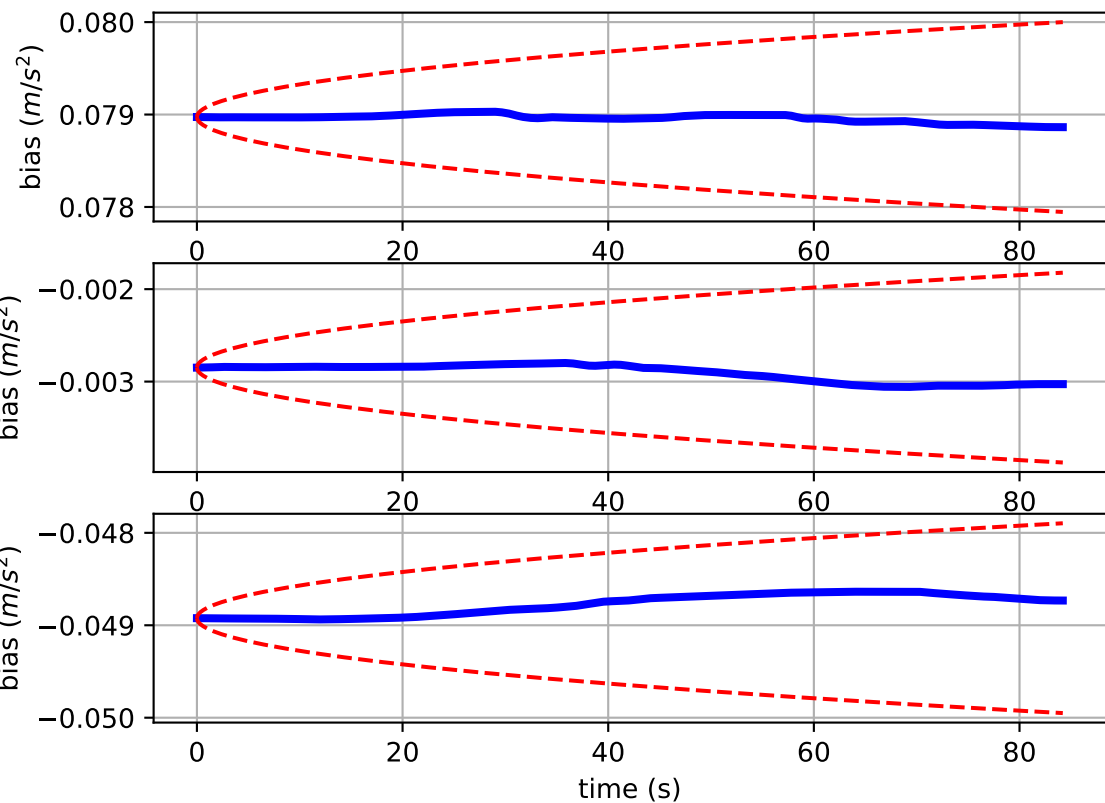
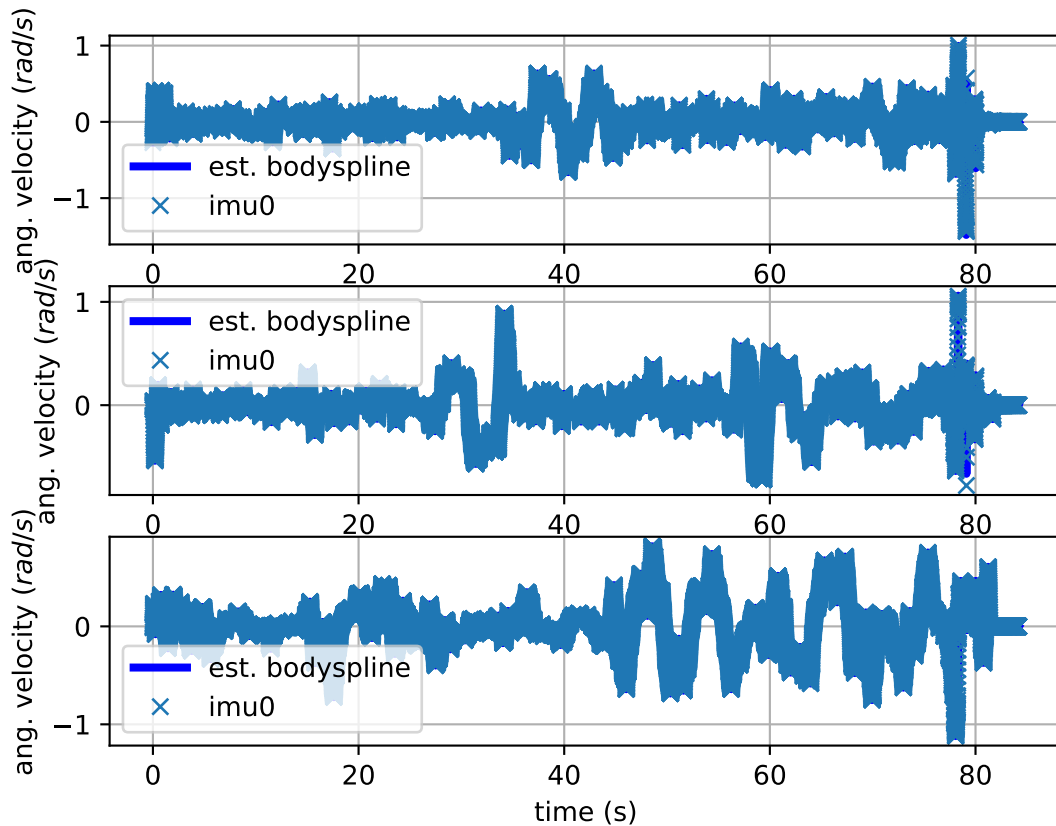Comparison of predicted and measured specific force (imu0 frame)
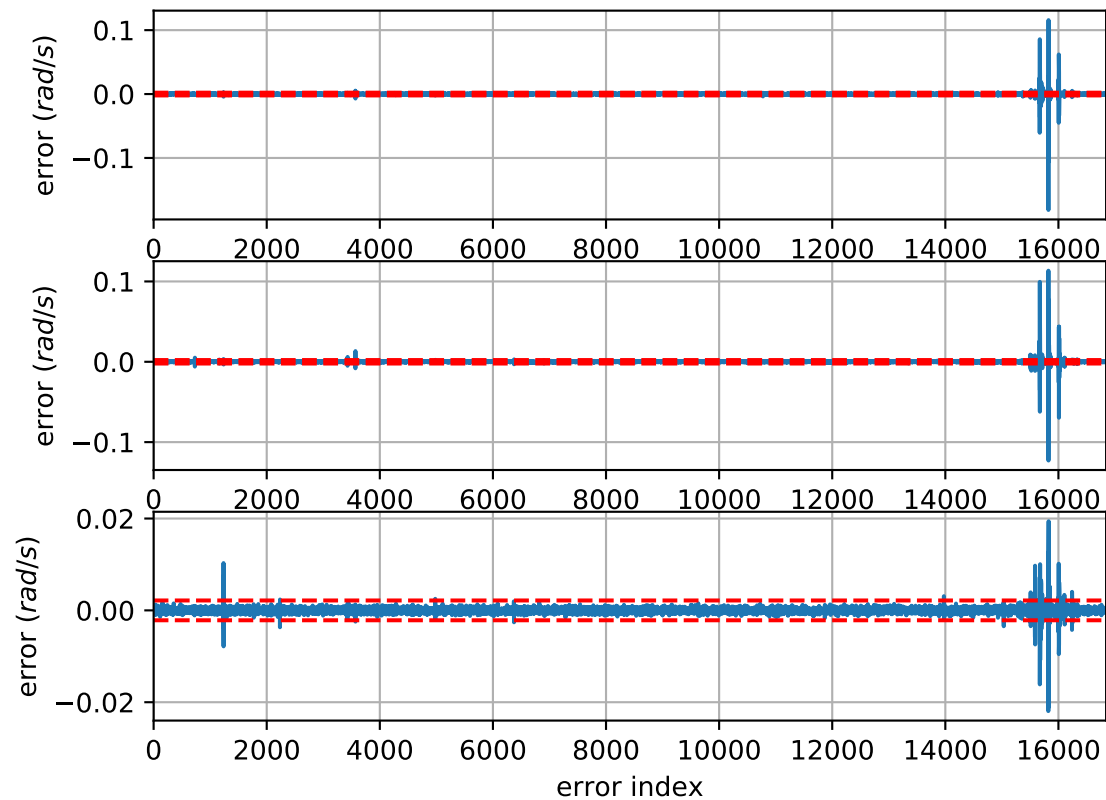
imu0: acceleration error
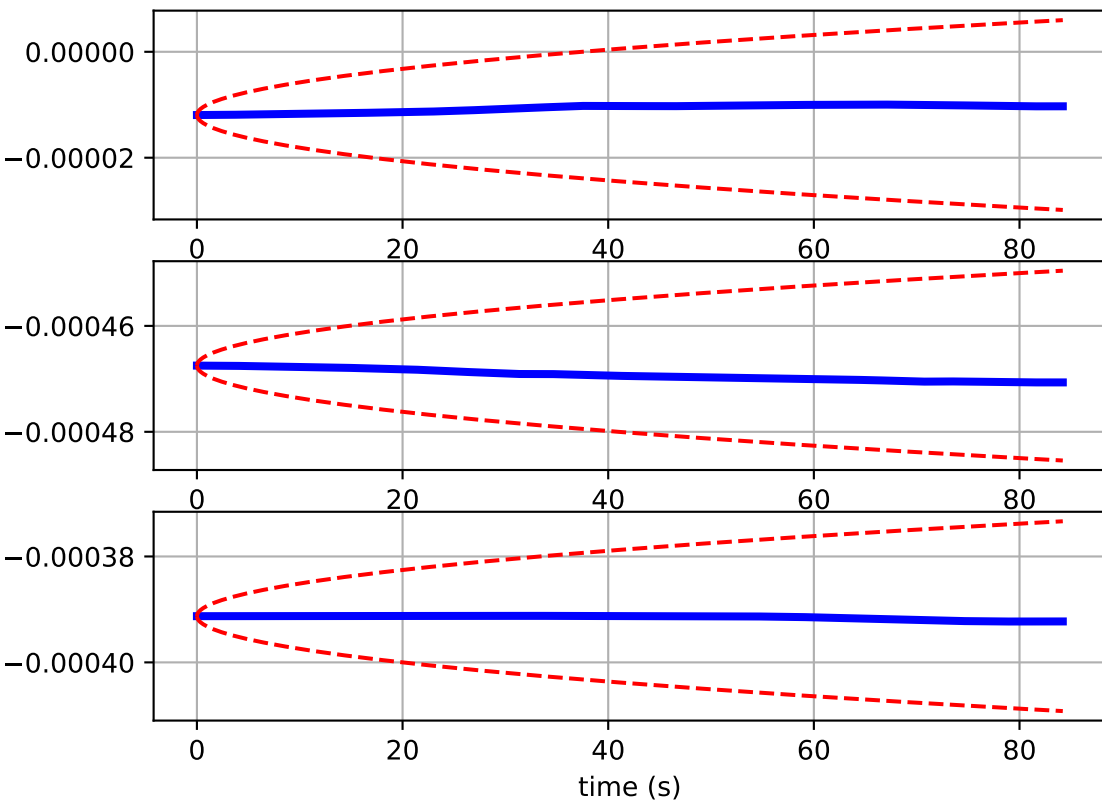
imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors