Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.668274461998, median 0.481523967314, std: 0.773459807783
Gyroscope error (imu0):   mean 2.51319408028, median 0.680145284382, std: 5.18022290966
Accelerometer error (imu0):   mean 0.912204853755, median 0.201830760274, std: 2.07949384291

Residuals

Reprojection error (cam0) [px]:   mean 0.668274461998, median 0.481523967314, std: 0.773459807783
Gyroscope error (imu0) [rad/s]:   mean 0.0904145692286, median 0.0244688794164, std: 0.186363491208
Accelerometer error (imu0) [m/s^2]: mean 0.370945301174, median 0.0820738585721, std: 0.845619782305

Transformation (cam0):

T_ci: (imu0 to cam0):
[[0.28460673 -0.66740685 -0.68816212 -0.12849895]
 [0.92173752 -0.00675148 0.38775555 0.13315853]
 [-0.26343682 -0.74466269 0.61325241 0.32129377]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[0.28460673 0.92173752 -0.26343682 -0.00152494]
 [-0.66740685 -0.00675148 -0.74466269 0.15439343]
 [-0.68816212 0.38775555 0.61325241 -0.33709525]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
-0.538154582641

Gravity vector in target coords: [m/s^2]
[3.62798686 7.91334522 4.51498634]

Calibration configuration
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cam0

```
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  Camera model: pinhole
  Focal length: [530.00468109, 521.86027041]
  Principal point: [428.96714026, 248.36783979]
  Distortion model: equidistant
  Distortion coefficients: [0.31205856, 0.23307093, -0.13151944, 0.12435412]
  Type: aprilgrid
  Tags:
    Rows: 6
    Cols: 6
    Size: 0.072 [m]
    Spacing 0.0216 [m]



IMU configuration
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IMU0:
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  Model: calibrated
  Update rate: 100.0
  Accelerometer:
    Noise density: 0.0406646927658
    Noise density (discrete): 0.406646927658
    Random walk: 0.00311311645065
  Gyroscope:
    Noise density: 0.00359759598107
    Noise density (discrete): 0.0359759598107
    Random walk: 0.000114424620336
  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]
```
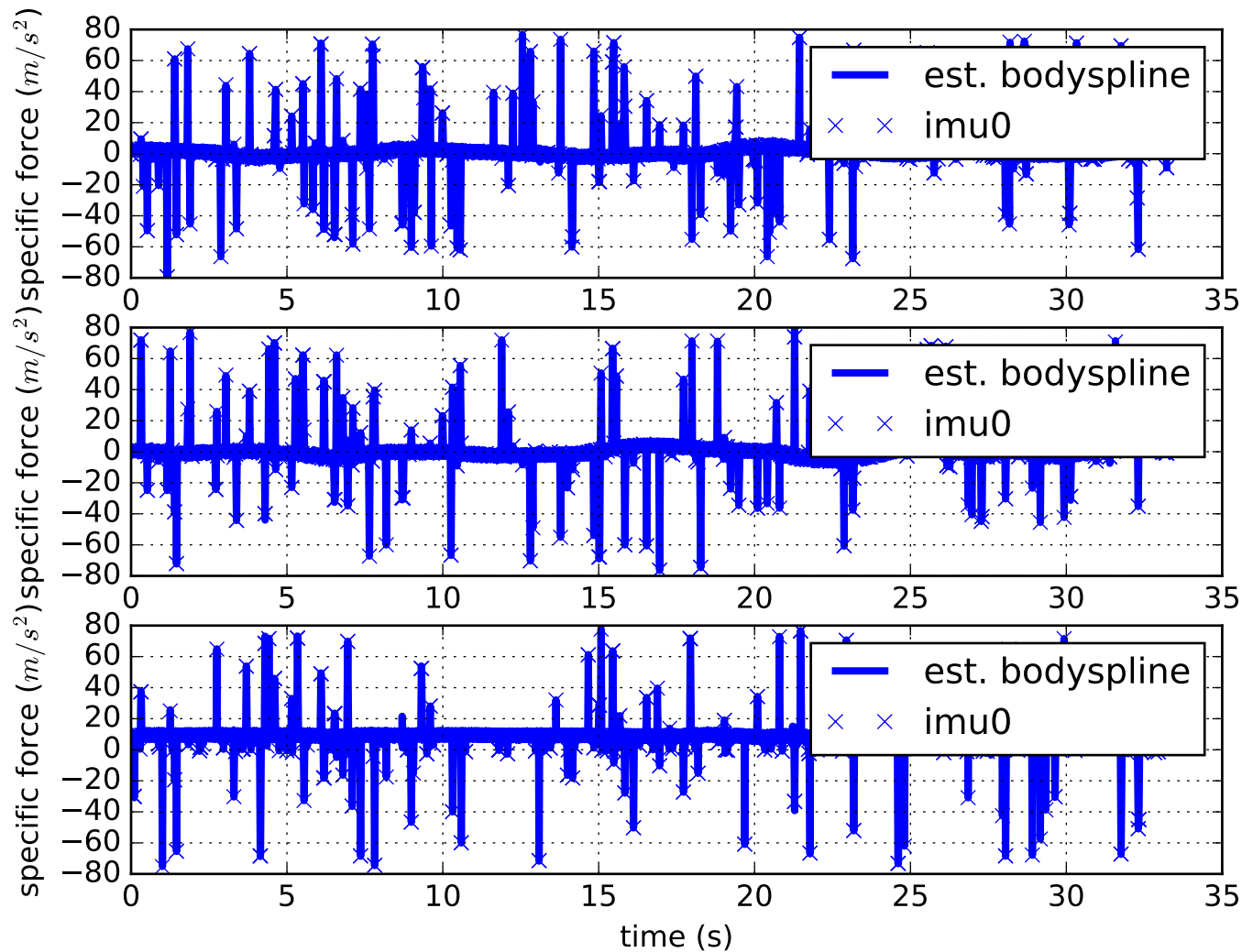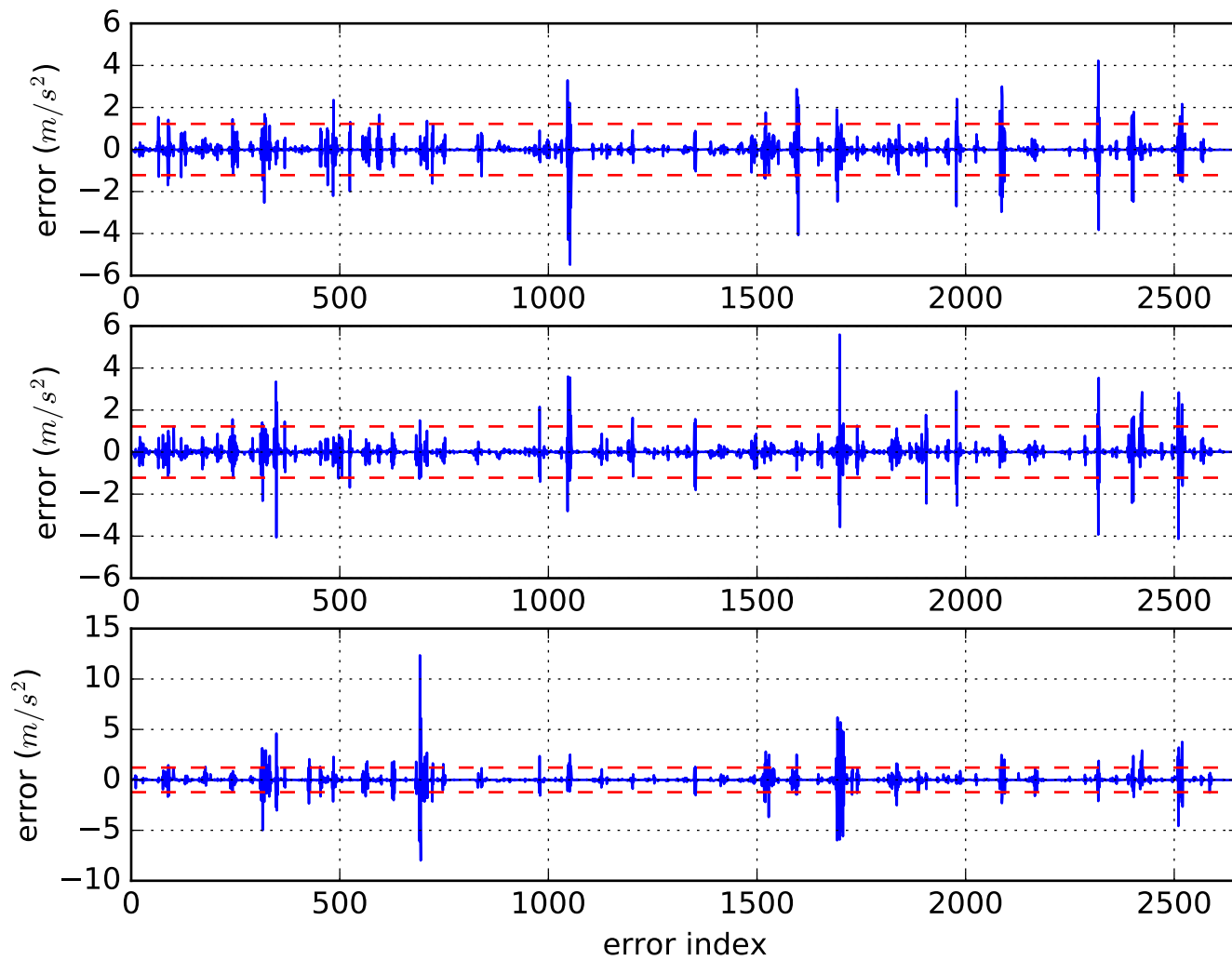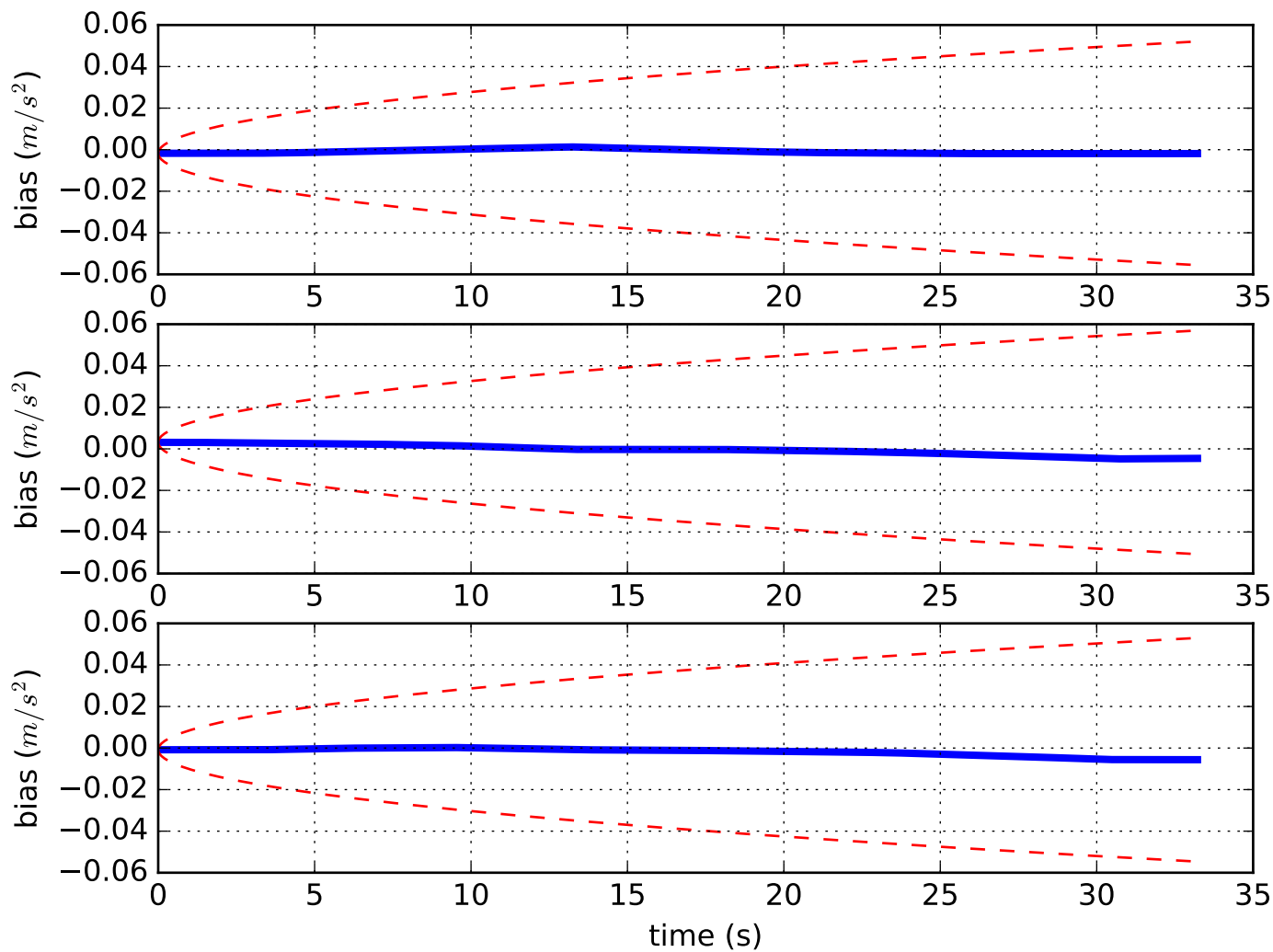
Comparison of predicted and measured specific force (imu0 frame)
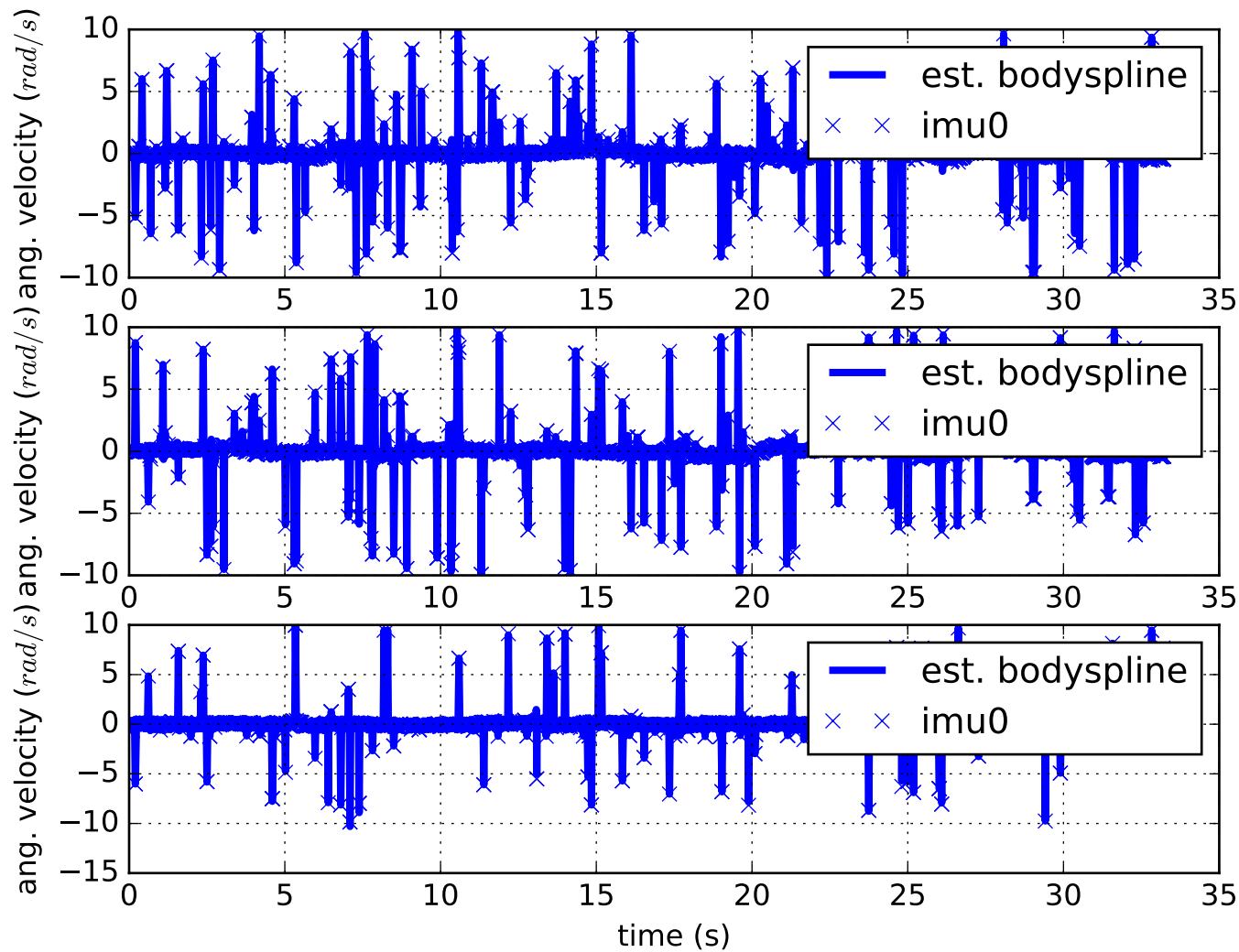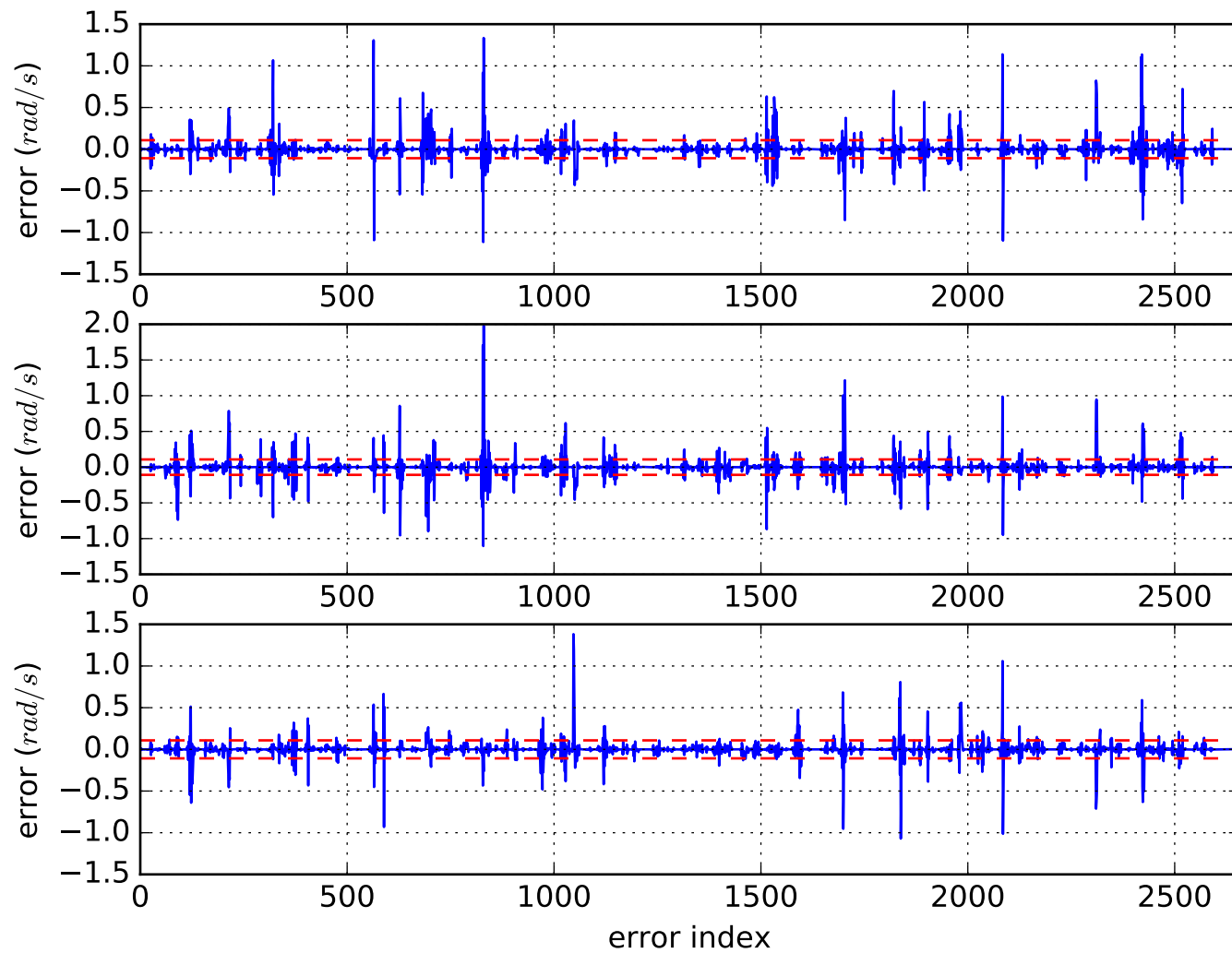
imu0: acceleration error

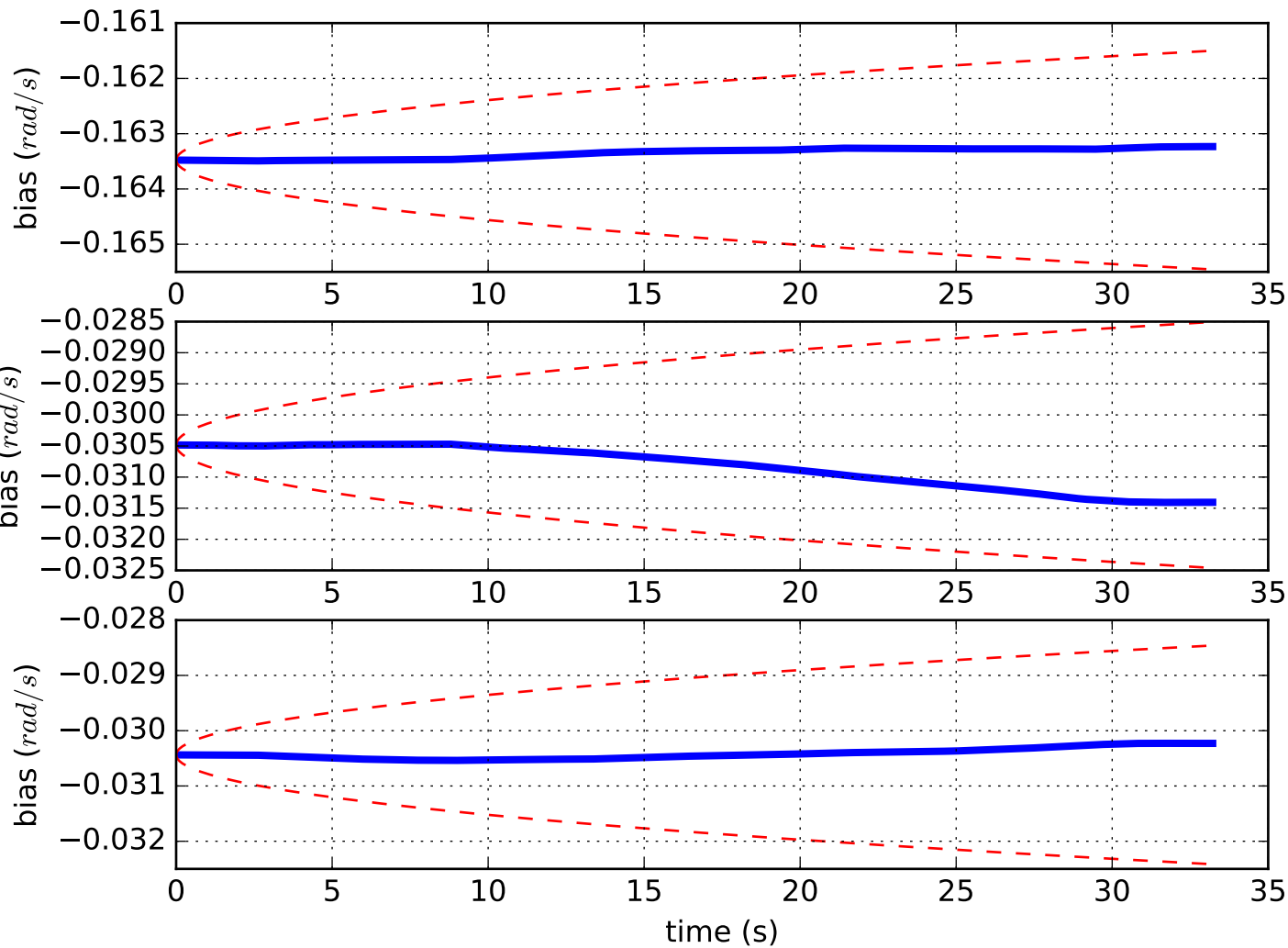imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors