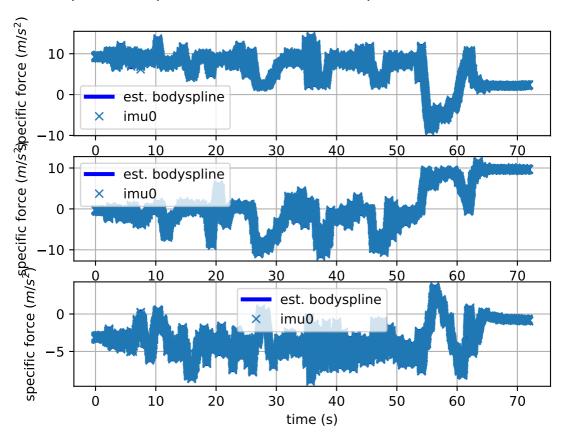
```
Calibration results
================
Normalized Residuals
-----
                          mean 0.4068389856313736, median 0.35019152049973784, std: 0.26813918
Reprojection error (cam0):
Gyroscope error (imu0):
                          mean 0.11010219799507329, median 0.0949146151684012, std: 0.067562486
Accelerometer error (imu0):
                           mean 0.3517593093338472, median 0.31929933142341543, std: 0.19736850
Residuals
                              mean 0.4068389856313736, median 0.35019152049973784, std: 0.26813
Reprojection error (cam0) [px]:
Gyroscope error (imu0) [rad/s]:
                              mean 0.007785401082586021, median 0.006711476801928803, std: 0.00
Accelerometer error (imu0) [m/s^2]: mean 0.04974627859509194, median 0.04515574449556558, std: 0.0
Transformation (cam0):
T ci: (imu0 to cam0):
[[ 0.01477499  0.99954017 -0.02647936  0.06553522]
[-0.99988927 0.01481672 0.00138036 -0.0199015 ]
[ 0.00177206  0.02645603  0.99964841 -0.00491211]
[ 0.
                       1.
         0.
                0.
T ic: (cam0 to imu0):
[[ 0.01477499 -0.99988927  0.00177206 -0.02085887]
[ 0.99954017  0.01481672  0.02645603 -0.06508026]
[-0.02647936 0.00138036 0.99964841 0.00667319]
١٥.
         0.
                0.
                        1.
timeshift cam0 to imu0: [s] (t imu = t cam + shift)
-5.358274956430555e-05
Gravity vector in target coords: [m/s^2]
[-0.02019335 -9.54999677 -2.22835745]
```

Calibration configuration

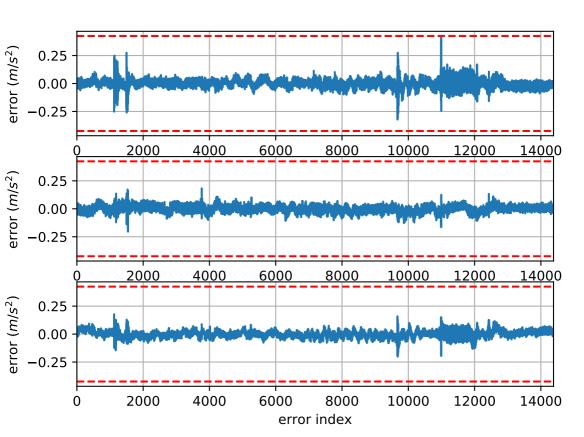
Camera model: pinhole Focal length: [458.9432286546919, 457.5637533402653] Principal point: [367.0272509347057, 249.3128033381081] Distortion model: radtan Distortion coefficients: [-0.2879529995338575, 0.0781311194952221, 0.00021265916642721963, -0.0001 Type: aprilgrid Tags: Rows: 6 Cols: 6 Size: 0.088 [m] Spacing 0.02639999999999996 [m] IMU configuration =========== IMU0: Model: calibrated Update rate: 200.0 Accelerometer: Noise density: 0.01 Noise density (discrete): 0.1414213562373095 Random walk: 0.0002 Gyroscope: Noise density: 0.005 Noise density (discrete): 0.07071067811865475 Random walk: 4e-06 Tib [1, 0, 0, 0, 1][0, 1, 0, 0.1] $[0. \ 0. \ 1. \ 0.]$ [0. 0. 0. 1.]]

time offset with respect to IMU0: 0.0 [s]

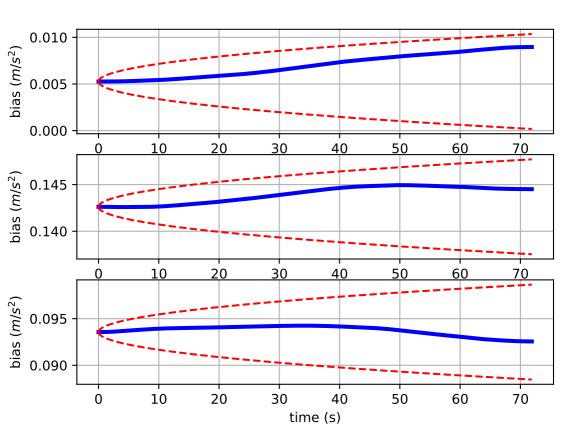
Comparison of predicted and measured specific force (imu0 frame)



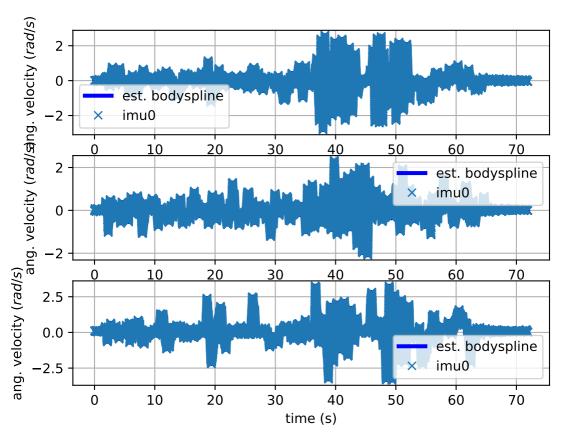
imu0: acceleration error



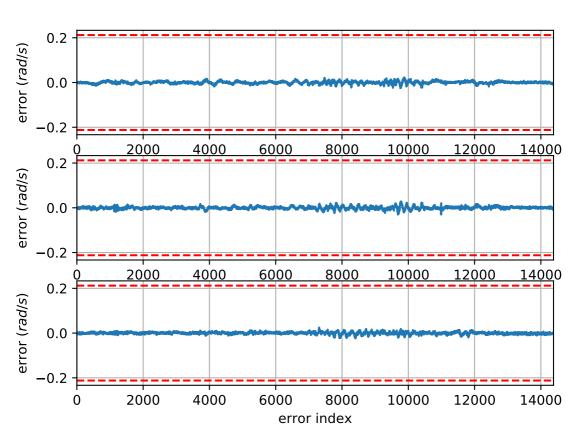
imu0: estimated accelerometer bias (imu frame)



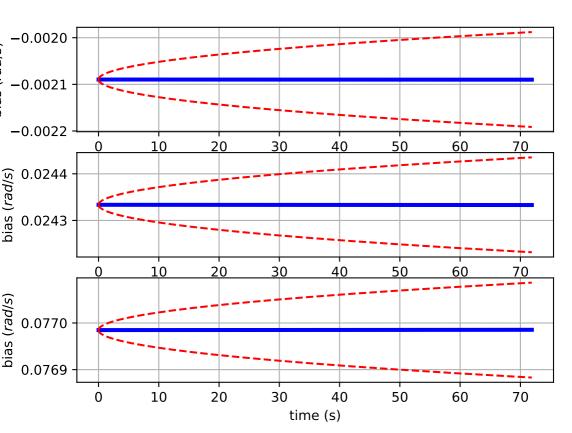
Comparison of predicted and measured angular velocities (body frame)



imu0: angular velocities error



imu0: estimated gyro bias (imu frame)



cam0: reprojection errors

