Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.301064067824, median 0.292093212612, std: 0.146046528159
Gyroscope error (imu0):   mean 0.174665346712, median 0.104449900036, std: 0.17523796231
Accelerometer error (imu0):   mean 0.195522698416, median 0.157219524987, std: 0.140639174587

Residuals

Reprojection error (cam0) [px]:   mean 0.301064067824, median 0.292093212612, std: 0.146046528159
Gyroscope error (imu0) [rad/s]:   mean 0.00089866679029, median 0.000537402857399, std: 0.000901612942065
Accelerometer error (imu0) [m/s^2]: mean 0.0118218337747, median 0.00950591980156, std: 0.00850342675118

Transformation (cam0):

T_ci: (imu0 to cam0):
[[0.00665775 -0.99990666 -0.01193067 -0.31302409]
 [0.02223236 0.012076   -0.99967989 0.15991158]
 [0.99973066 0.00639037 0.02231069 -0.46545314]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[0.00665775 0.02223236 0.99973066 0.46385661]
 [-0.99990666 0.012076   0.00639037 -0.31195155]
 [-0.01193067 -0.99967989 0.02231069 0.16651039]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
0.00595802104811

Gravity vector in target coords: [m/s^2]
[0.02624373 -9.80651119 0.00851034]

Calibration configuration
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cam0

Camera model: pinhole
Focal length: [637.0102235086177, 636.5671950687336]
Principal point: [653.6378859316724, 362.8854879948024]
Distortion model: radtan
Distortion coefficients: [-0.044682744054906895, 0.024952434249305173, -6.46507710571878e-05, 0.001005164472103523]
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.0352 [m]
Spacing 0.01056 [m]

IMU configuration
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IMU0:

Model: calibrated
Update rate: 100.0
Accelerometer:
Noise density: 0.00604627179884
Noise density (discrete): 0.0604627179884
Random walk: 0.000170413289485
Gyroscope:
Noise density: 0.000514507775702
Noise density (discrete): 0.00514507775702
Random walk: 1.41213835334e-05

```
T_ib (imu0 to imu0)
[[ 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]
```
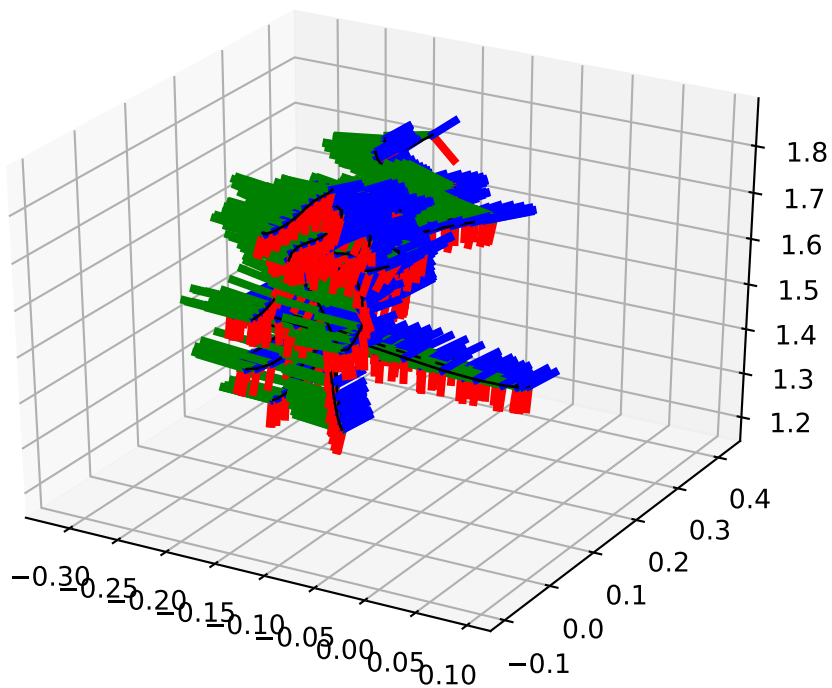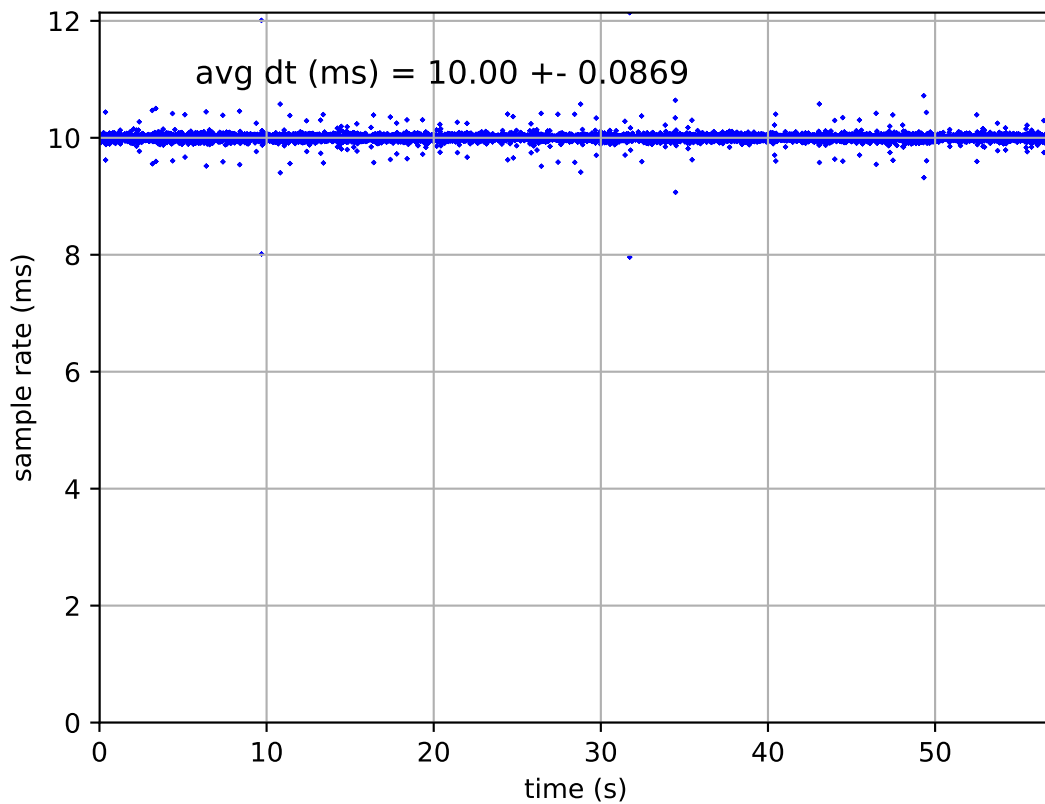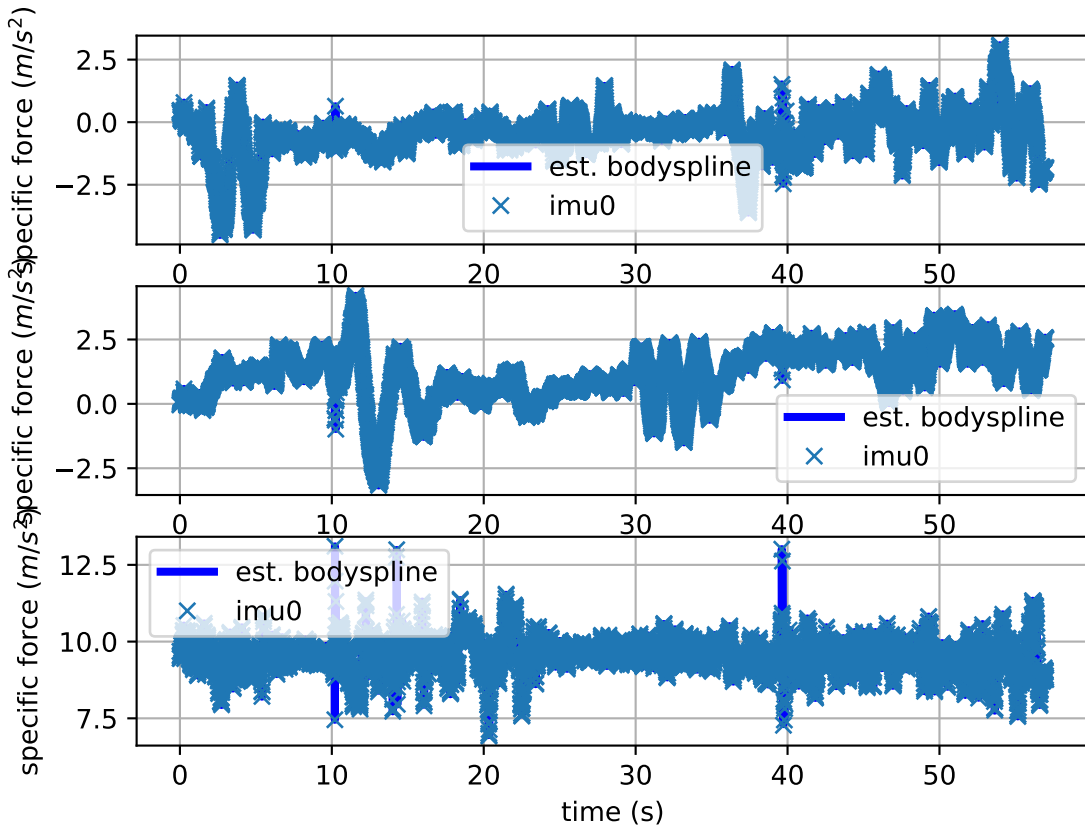
imu0: estimated poses

imu0: sample inertial rate

avg dt (ms) = 10.00 +- 0.0869
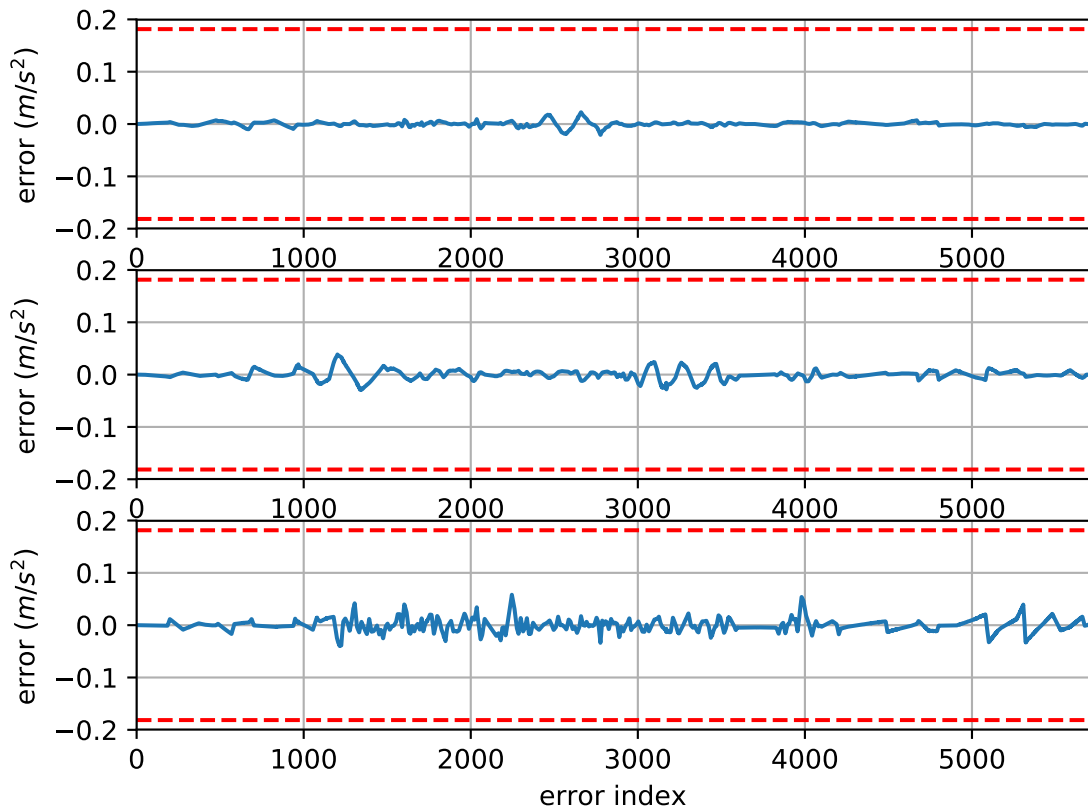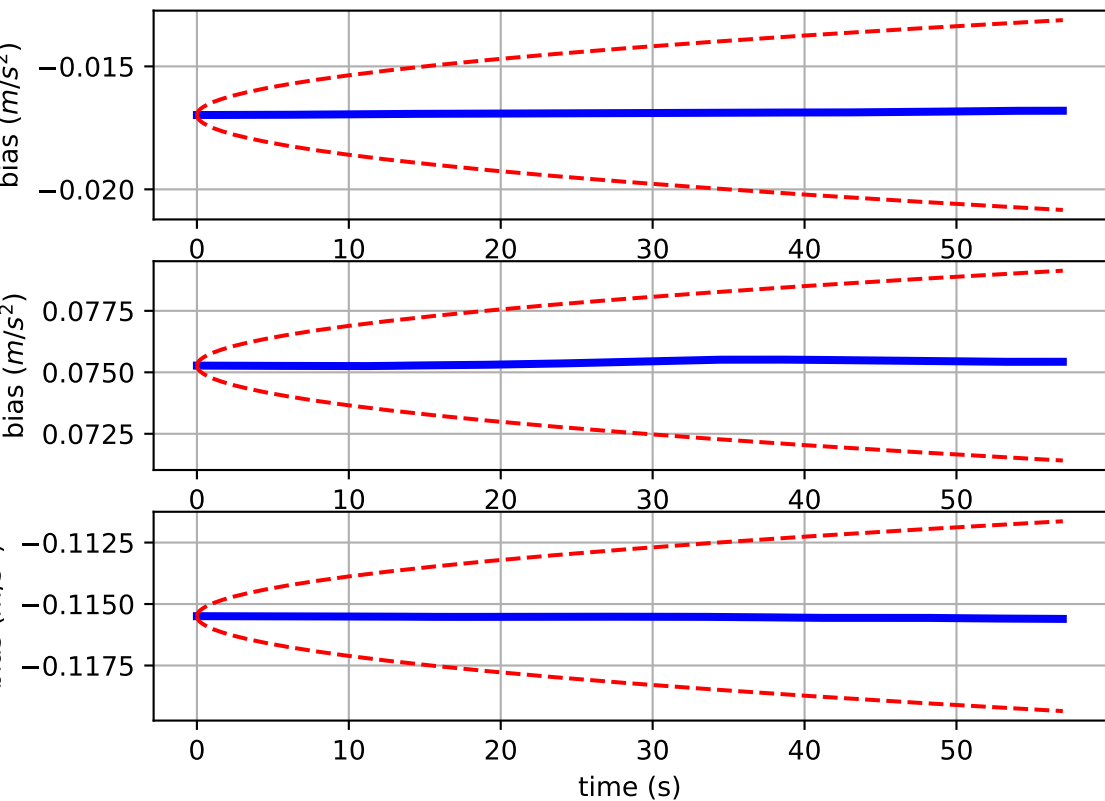
Comparison of predicted and measured specific force (imu0 frame)
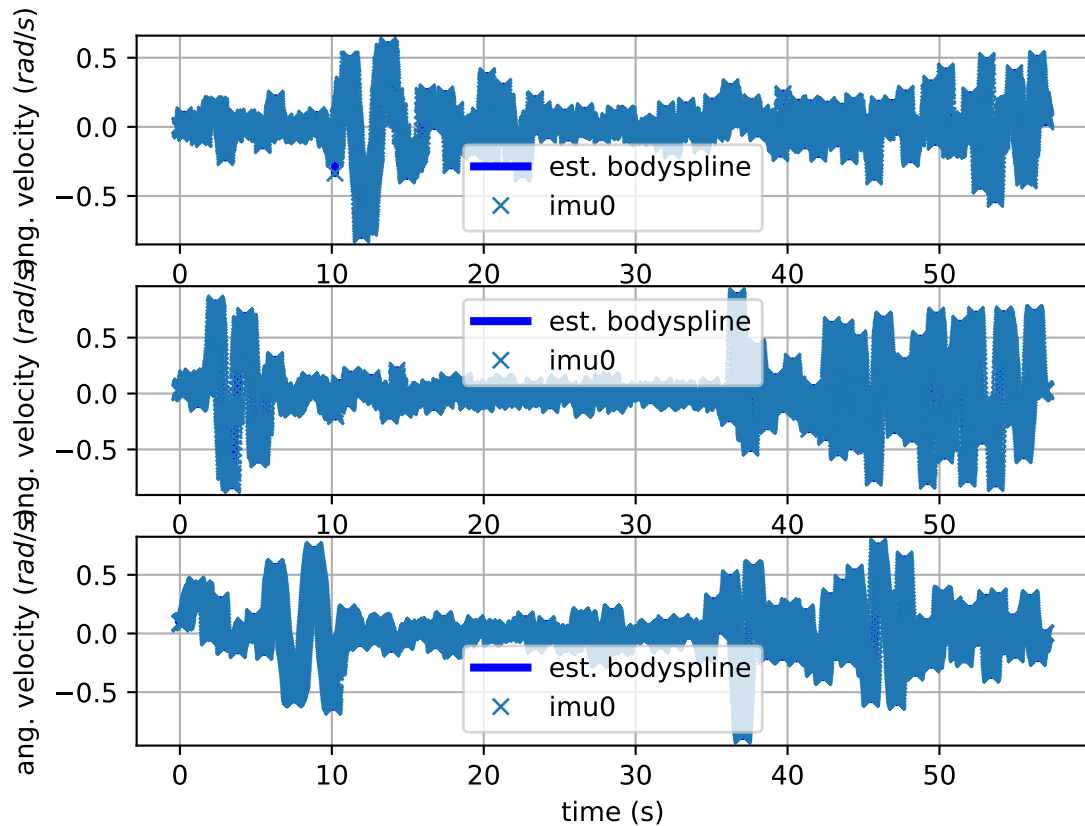
imu0: acceleration error

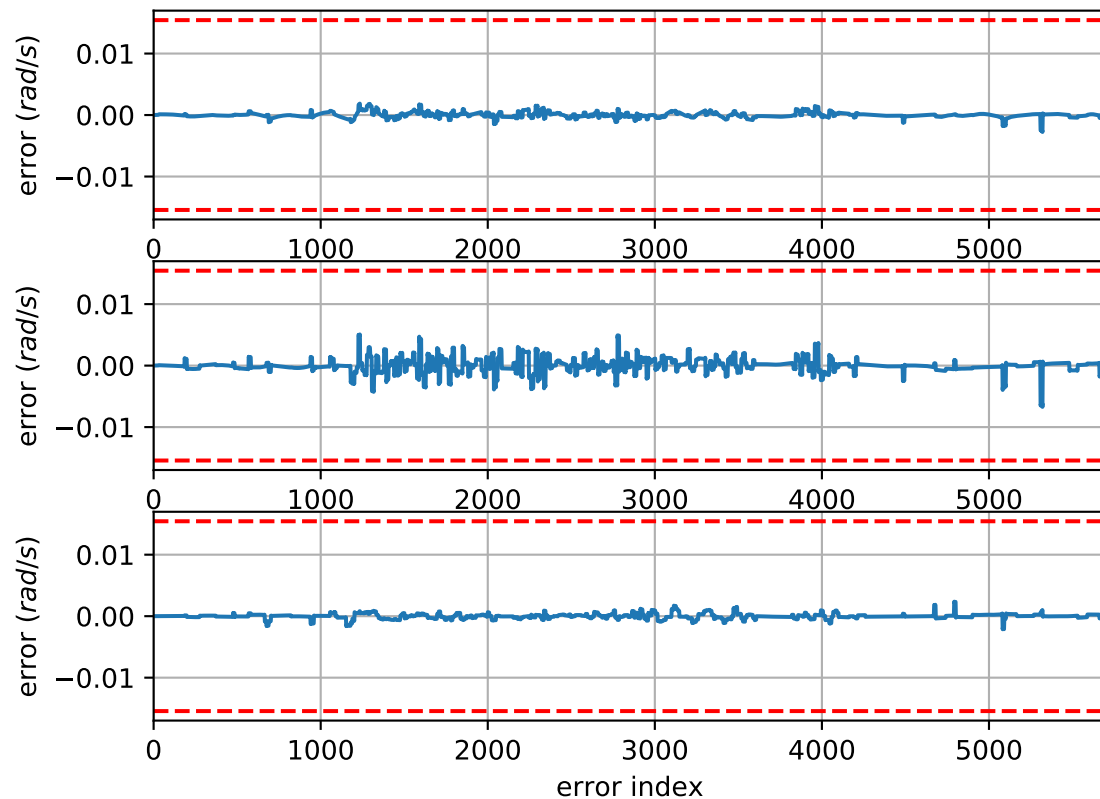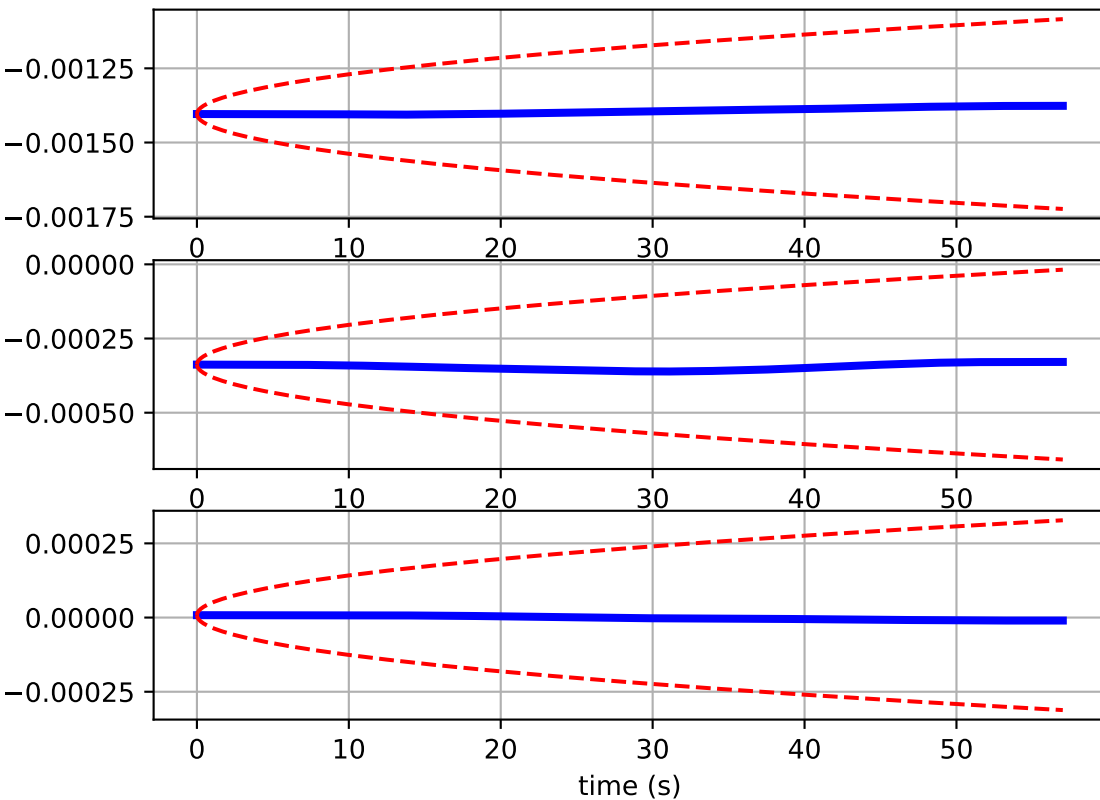imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors