Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.40683936316877956, median 0.3501845313970696, std: 0.26813884451818754
Gyroscope error (imu0):   mean 0.11010212195242976, median 0.0949145130938065, std: 0.06756249064730994
Accelerometer error (imu0):   mean 0.3517593994122728, median 0.3192994341170933, std: 0.19736854107420146

Residuals

Reprojection error (cam0) [px]:   mean 0.40683936316877956, median 0.3501845313970696, std:
0.26813884451818754
Gyroscope error (imu0) [rad/s]:   mean 0.007785395705559131, median 0.006711469584164992, std:
0.0047773895290565555
Accelerometer error (imu0) [m/s^2]: mean 0.049746291334105075, median 0.04515575901864478, std:
0.0279121267572927

Transformation (cam0):

T_ci: (imu0 to cam0):
[[0.014775   0.99954017 -0.02647936 0.0655352]
 [-0.99988927 0.01481673 0.00138037 -0.01990149]
 [0.00177207 0.02645603 0.99964841 -0.00491213]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[0.014775   -0.99988927 0.00177207 -0.02085886]
 [0.99954017 0.01481673 0.02645603 -0.06508024]
 [-0.02647936 0.00138037 0.99964841 0.0066732]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
-5.3580886699517466e-05

Gravity vector in target coords: [m/s^2]
[-0.0201935 -9.54999678 -2.22835739]

Calibration configuration
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cam0

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, -0.0001221450347654466]
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.088 [m]
Spacing 0.026399999999999996 [m]

IMU configuration
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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

```
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]
```
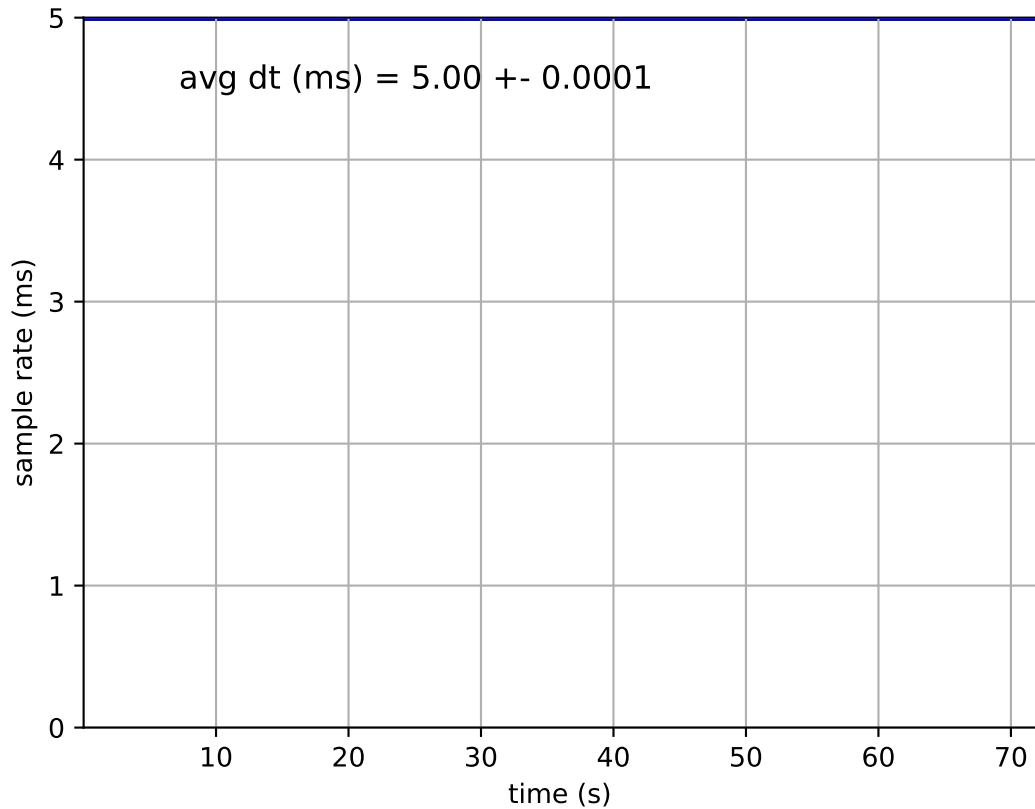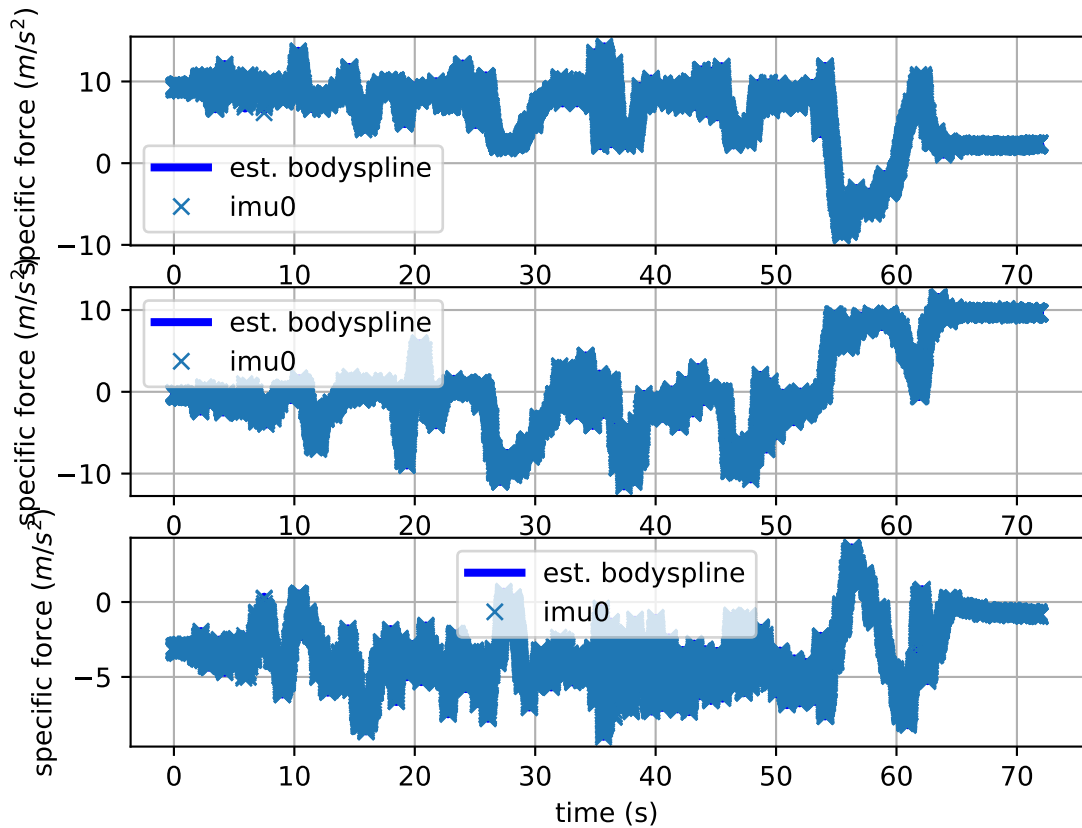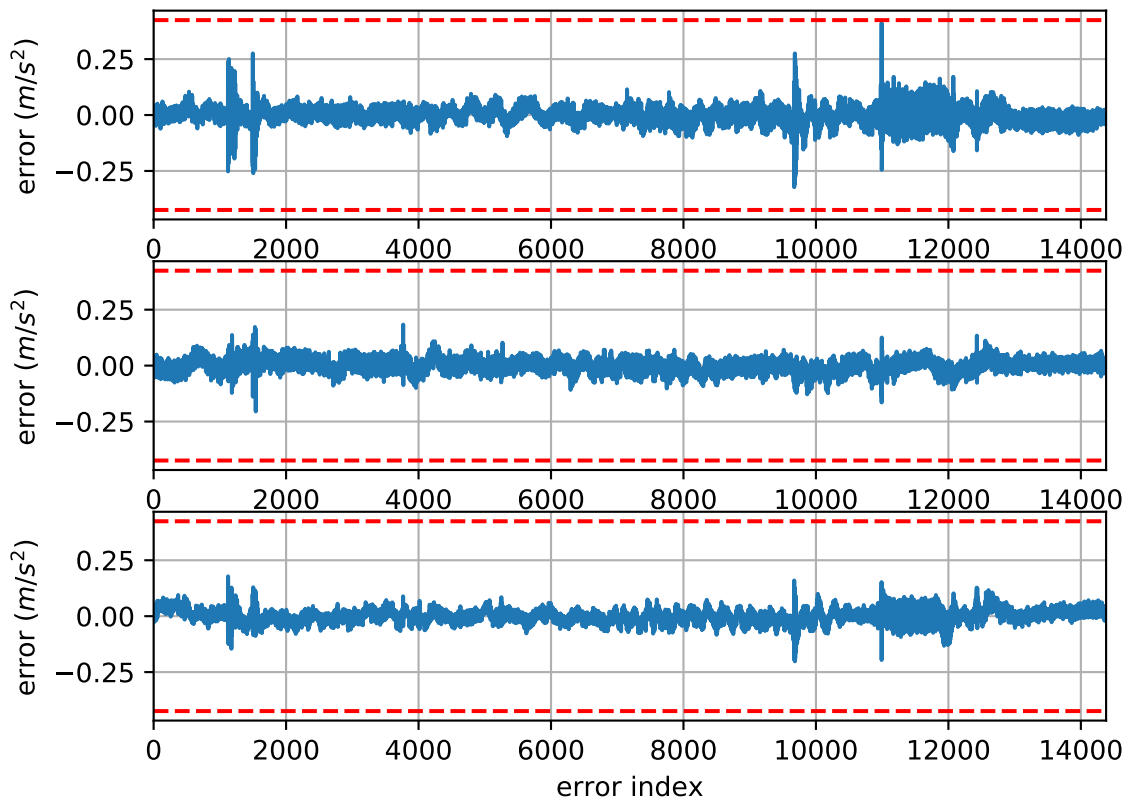
imu0: estimated poses
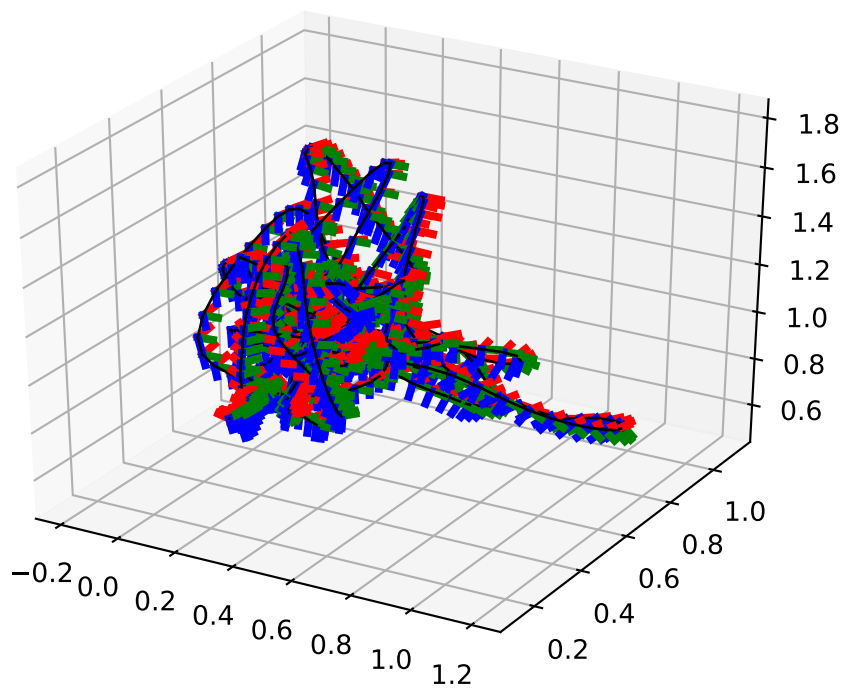
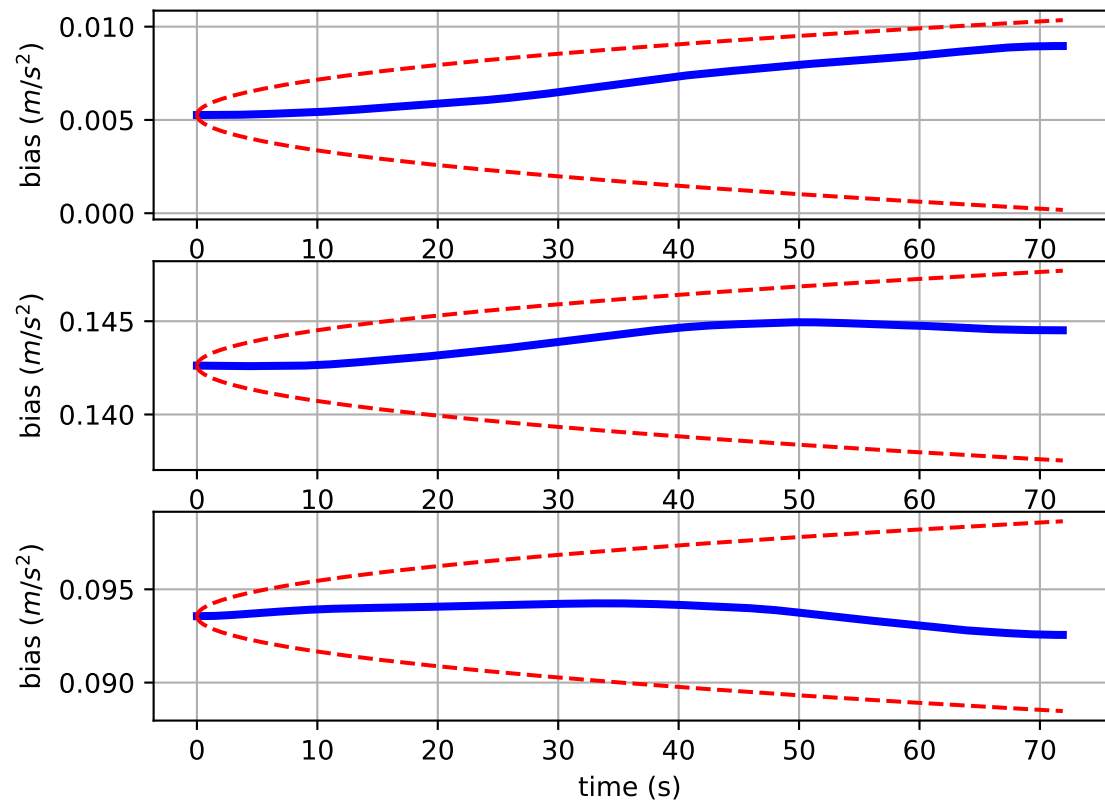imu0: sample inertial rate

avg dt (ms) = 5.00 +- 0.0001

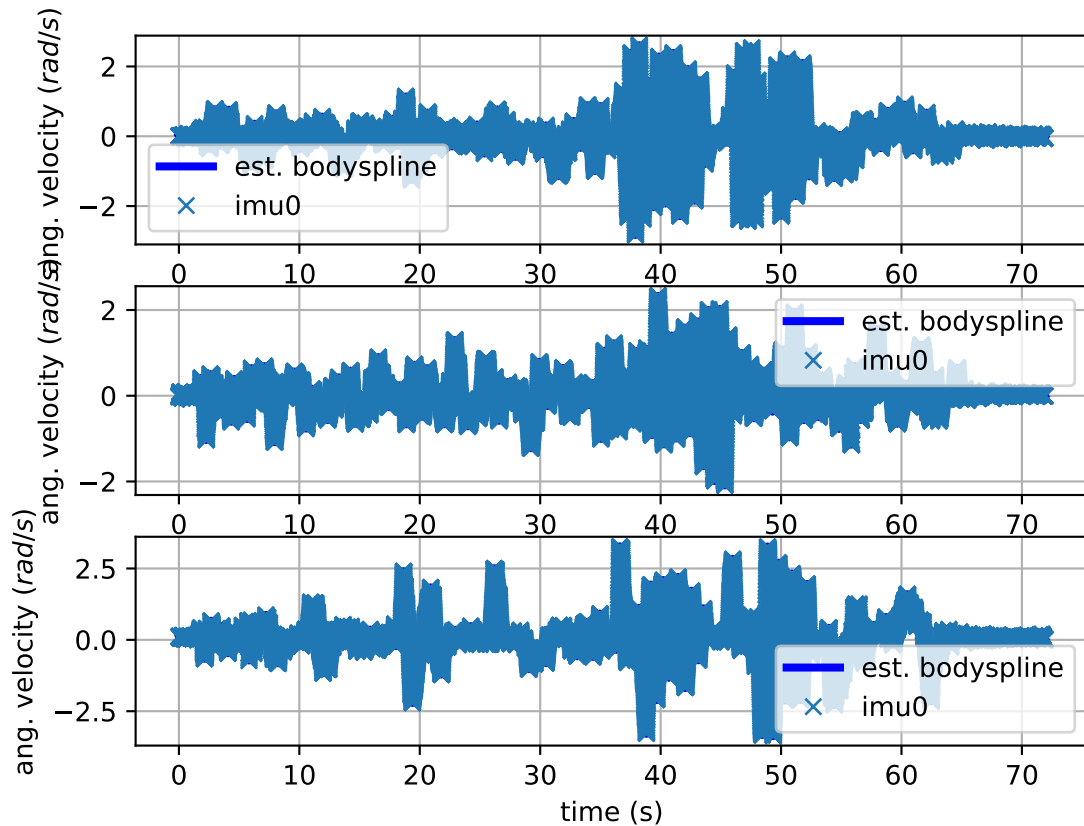Comparison of predicted and measured specific force (imu0 frame)
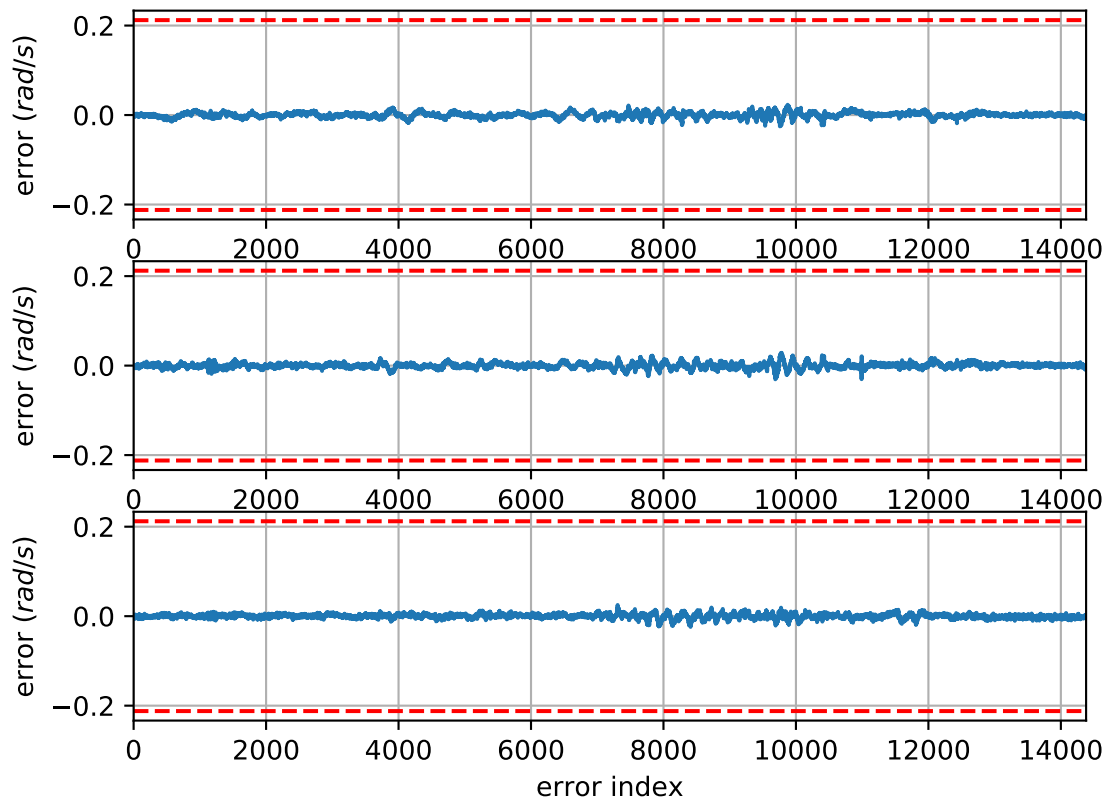
imu0: acceleration error
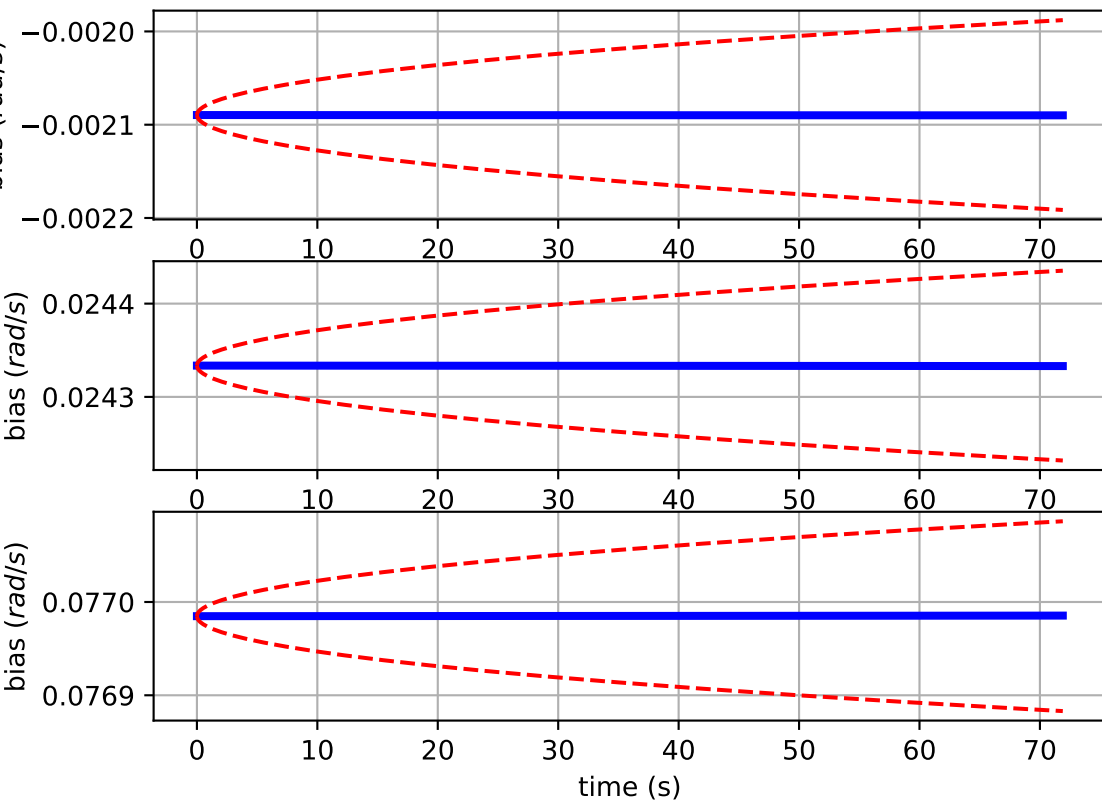
imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors