Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 25.9008365201, median 12.7388888944, std: 40.4459680516
Gyroscope error (imu0):   mean 22.3495890093, median 15.9900150652, std: 16.0865532223
Accelerometer error (imu0):   mean 26.2332911481, median 21.723982669, std: 17.8422120111

Residuals

Reprojection error (cam0) [px]:   mean 25.9008365201, median 12.7388888944, std: 40.4459680516
Gyroscope error (imu0) [rad/s]:   mean 0.107274469876, median 0.0767495271932, std: 0.0772128949814
Accelerometer error (imu0) [m/s^2]: mean 1.4839790451, median 1.22889403677, std: 1.00930792835

Transformation (cam0):

T_ci: (imu0 to cam0):
[[-0.08424277 0.99642167 -0.00685673 0.33696385]
 [-0.99178169 -0.08451148 -0.09605674 0.04963892]
 [-0.09629249 -0.00129171 0.99535224 0.19475509]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[-0.08424277 -0.99178169 -0.09629249 0.09637119]
 [0.99642167 -0.08451148 -0.00129171 -0.33131146]
 [-0.00685673 -0.09605674 0.99535224 -0.18677129]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
1.5340591444875307

Gravity vector in target coords: [m/s^2]
[-0.62613008 0.37217567 -9.77946161]

Calibration configuration

  Camera model: pinhole
  Focal length: [584.7399294374125, 584.117527258626]
  Principal point: [317.85650050808607, 237.29499445403727]
  Distortion model: radtan
  Distortion coefficients: [-0.04635982092303866, -0.10432387263456015, -0.0016201106528649408, -0.00
  Type: checkerboard
  Rows
    Count: 6
    Distance: 0.07 [m]
  Cols
    Count: 7
    Distance: 0.07 [m]

IMU configuration
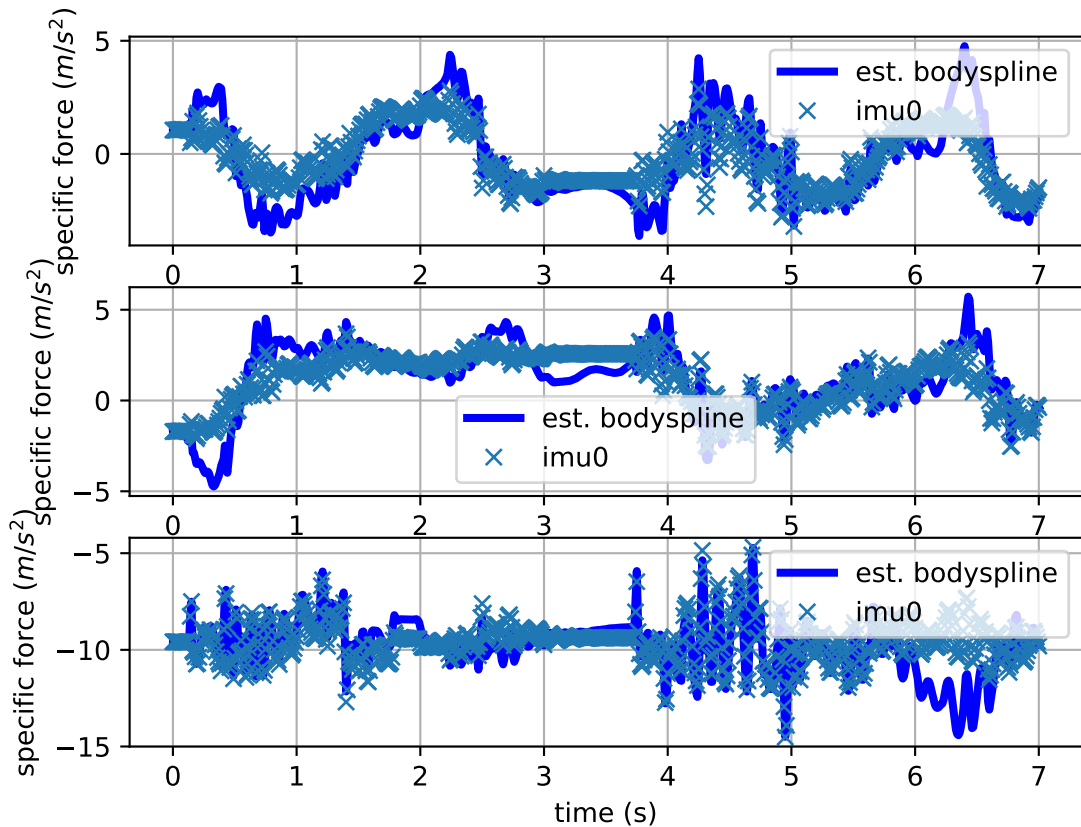=================

IMU0:

  Model: calibrated
  Update rate: 200.0
  Accelerometer:
    Noise density: 0.004
    Noise density (discrete): 0.0565685424949
    Random walk: 0.006
  Gyroscope:
    Noise density: 0.0003394
    Noise density (discrete): 0.00479984083069
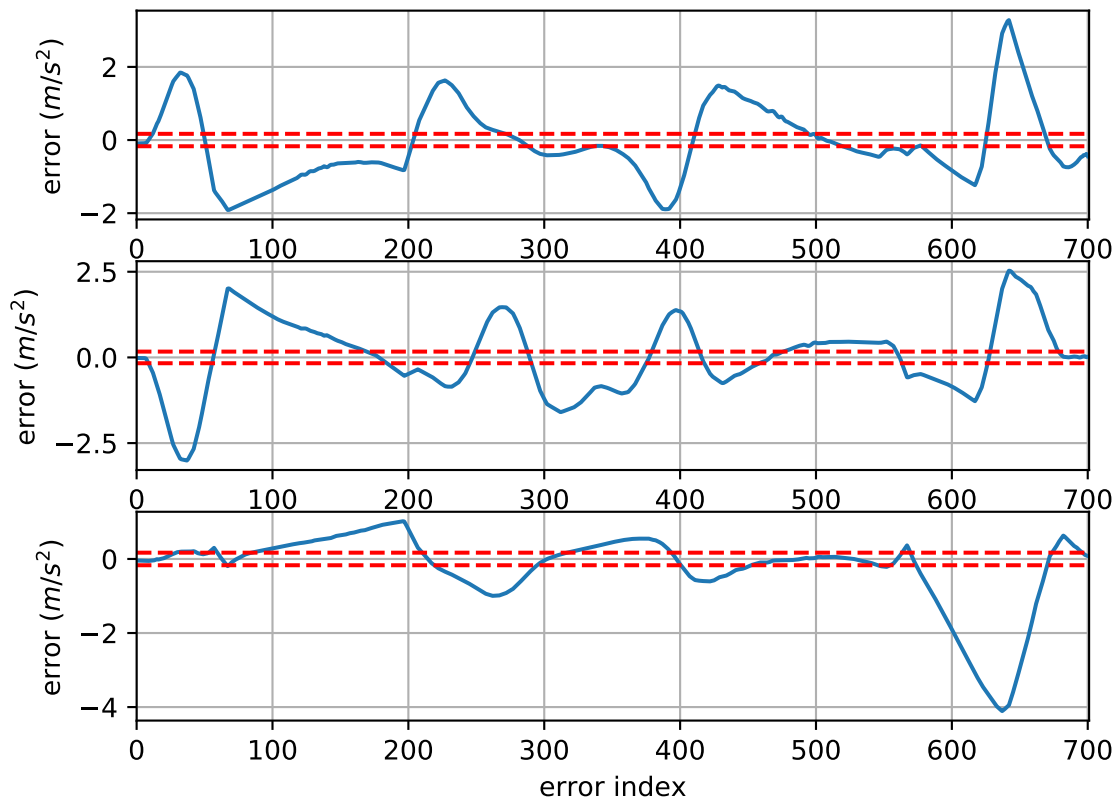   Random walk: 3.8785e-05
  T_i_b
    [[1. 0. 0. 0.]
     [0. 1. 0. 0.]
     [0. 0. 1. 0.]
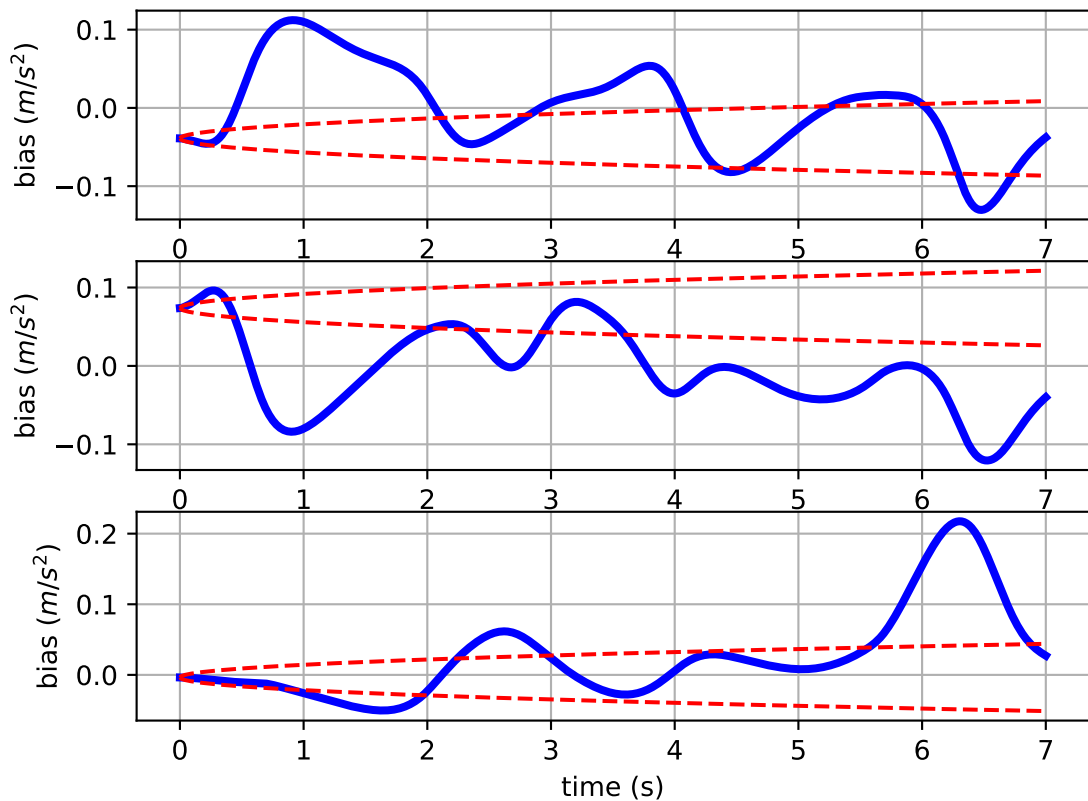   [0. 0. 0. 1.]]
  time offset with respect to IMU0: 0.0 [s]

Comparison of predicted and measured specific force (imu0 frame)

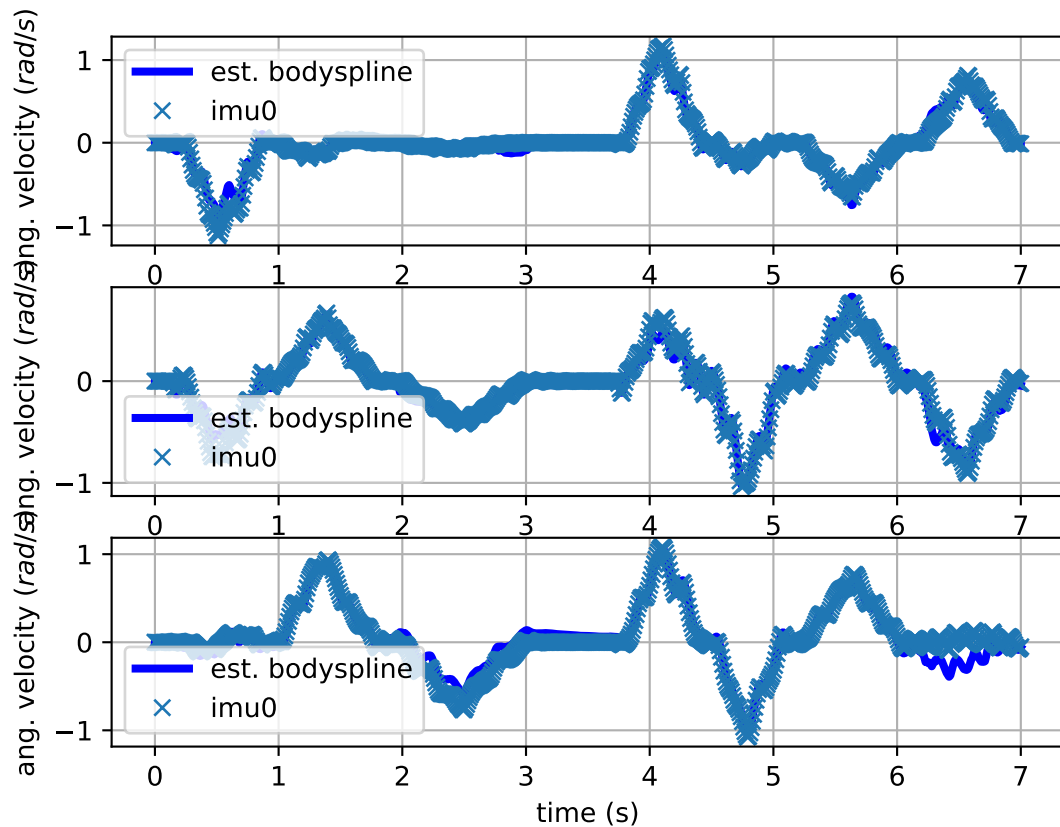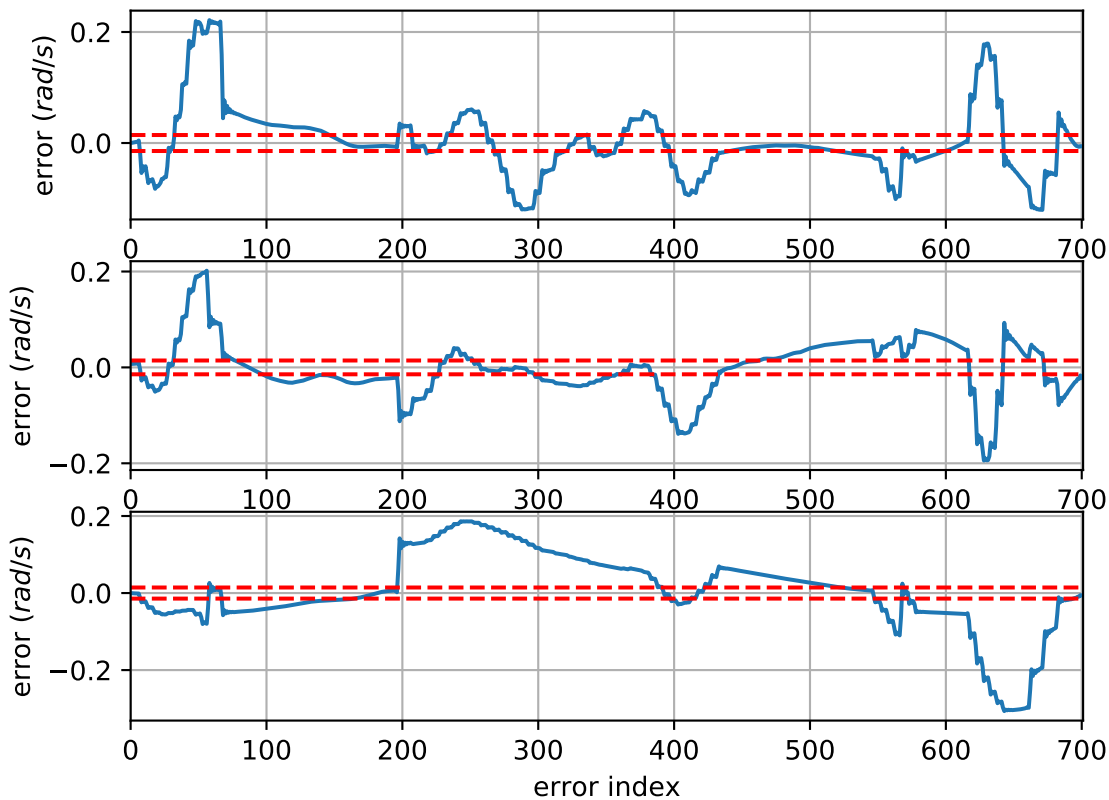imu0: acceleration error
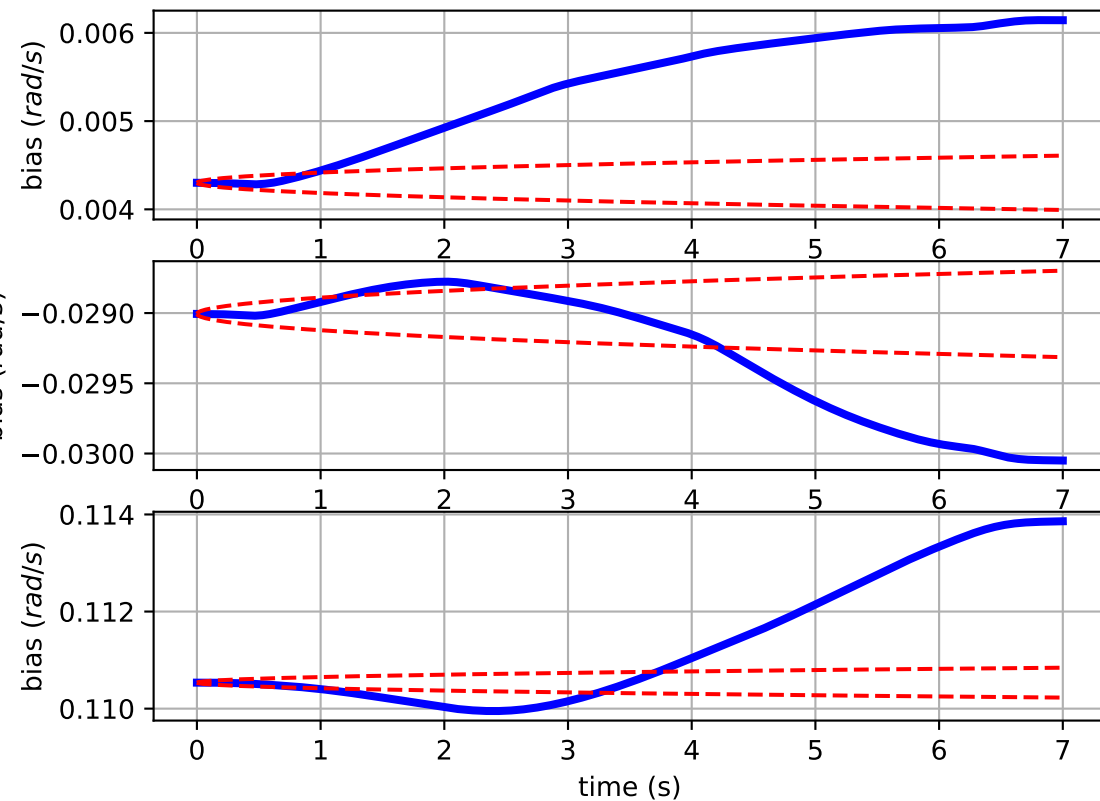
imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors