Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.045572406739, median 0.0419697162195, std: 0.0255776449664
Gyroscope error (imu0):   mean 0.0689976620843, median 0.0487547471446, std: 0.0605975130779
Accelerometer error (imu0):   mean 0.968547774275, median 0.2309237286, std: 1.56042965344

Residuals

Reprojection error (cam0) [px]:   mean 0.045572406739, median 0.0419697162195, std: 0.0255776449664
Gyroscope error (imu0) [rad/s]:   mean 0.00487887147458, median 0.0034474812321, std: 0.00428489124
Accelerometer error (imu0) [m/s^2]: mean 0.136973339819, median 0.0326575468859, std: 0.2206780779

Transformation (cam0):

T_ci: (imu0 to cam0):
[[0.99997223 0.00203342 0.00717013 -0.04071191]
 [-0.00197117 0.9999604 -0.00867817 -0.00522268]
 [-0.00718749 0.00866379 0.99993664 -0.0028997]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[0.99997223 -0.00197117 -0.00718749 0.04067965]
 [0.00203342 0.9999604   0.00866379 0.00533038]
 [0.00717013 -0.00867817 0.99993664 0.0031461]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
0.0014042984999845167

Gravity vector in target coords: [m/s^2]
[9.80430982 -0.20369297 0.0494059]

Calibration configuration

  Camera model: pinhole
  Focal length: [468.2527687453535, 468.3265694180005]
  Principal point: [364.91196913276707, 215.81303741968622]
  Distortion model: equidistant
  Distortion coefficients: [0.011135829319036753, -0.05338166866546771, 0.15329931633590166, -0.1346
  Type: checkerboard
  Rows
    Count: 7
    Distance: 0.07 [m]
  Cols
   Count: 6
    Distance: 0.07 [m]

IMU configuration
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IMU0:

  Model: calibrated
  Update rate: 200.0
  Accelerometer:
    Noise density: 0.01
    Noise density (discrete): 0.141421356237
    Random walk: 0.0002
  Gyroscope:
    Noise density: 0.005
    Noise density (discrete): 0.0707106781187
    Random walk: 4e-06
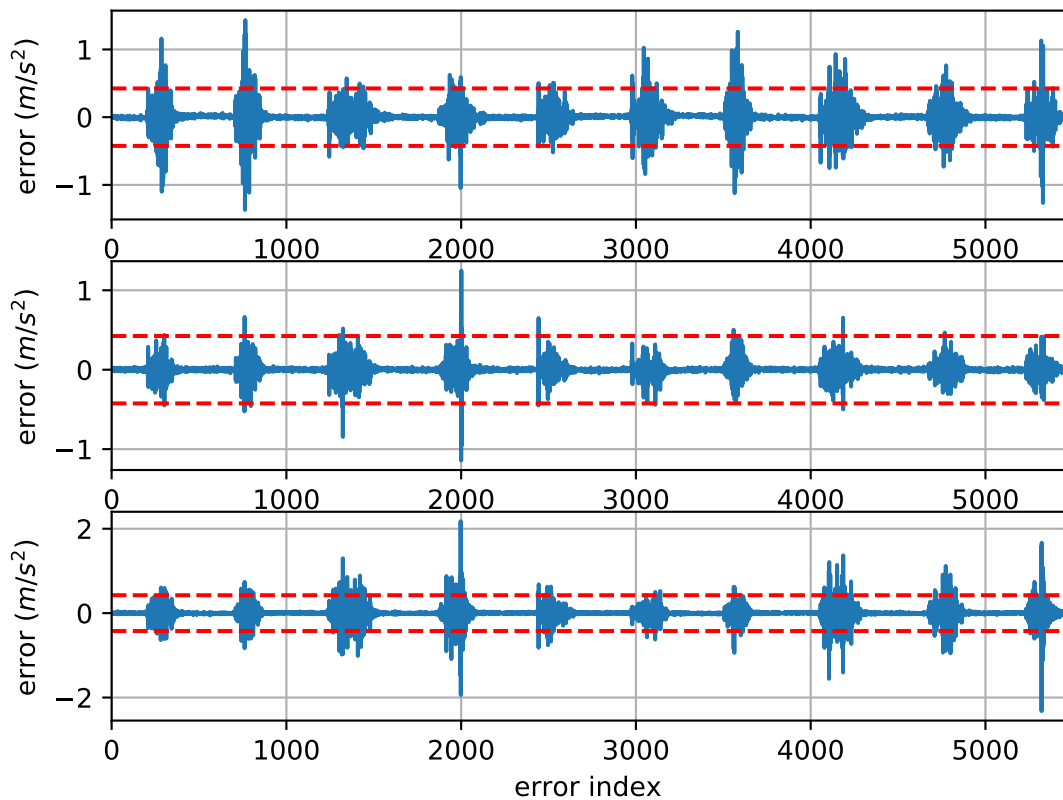 T_i_b
    [[1. 0. 0. 0.]
     [0. 1. 0. 0.]
     [0. 0. 1. 0.]
     [0. 0. 0. 1.]]
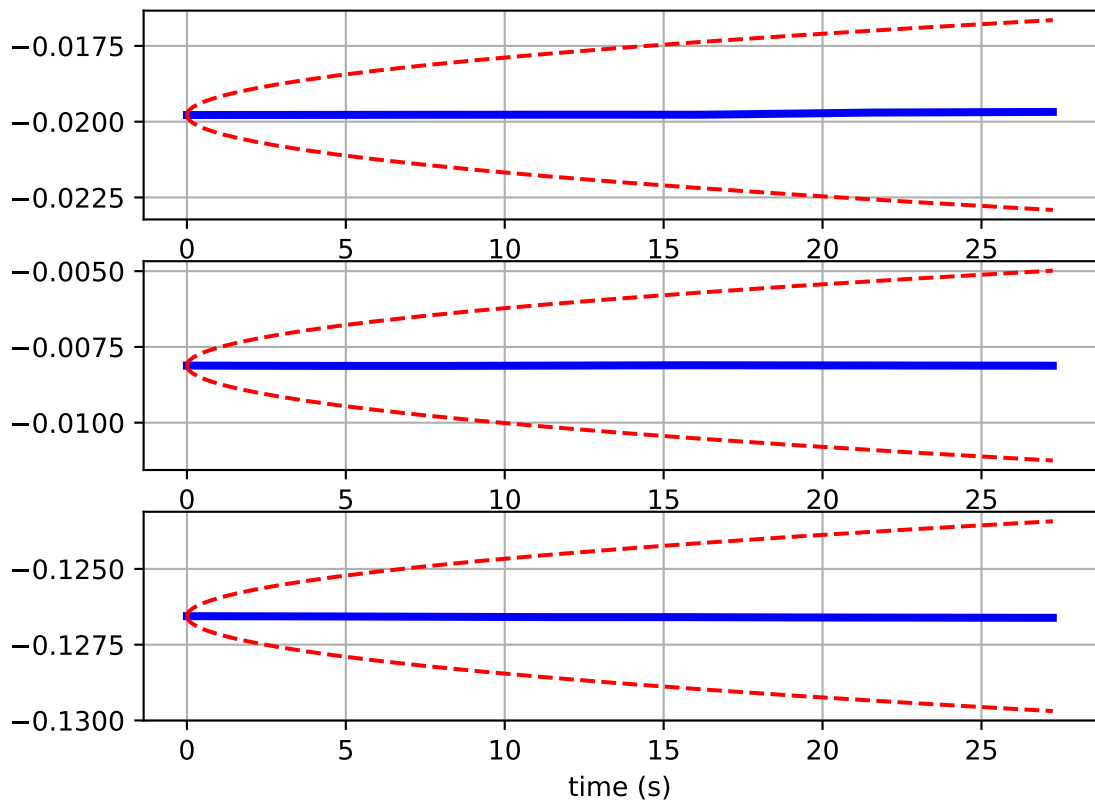 time offset with respect to IMU0: 0.0 [s]

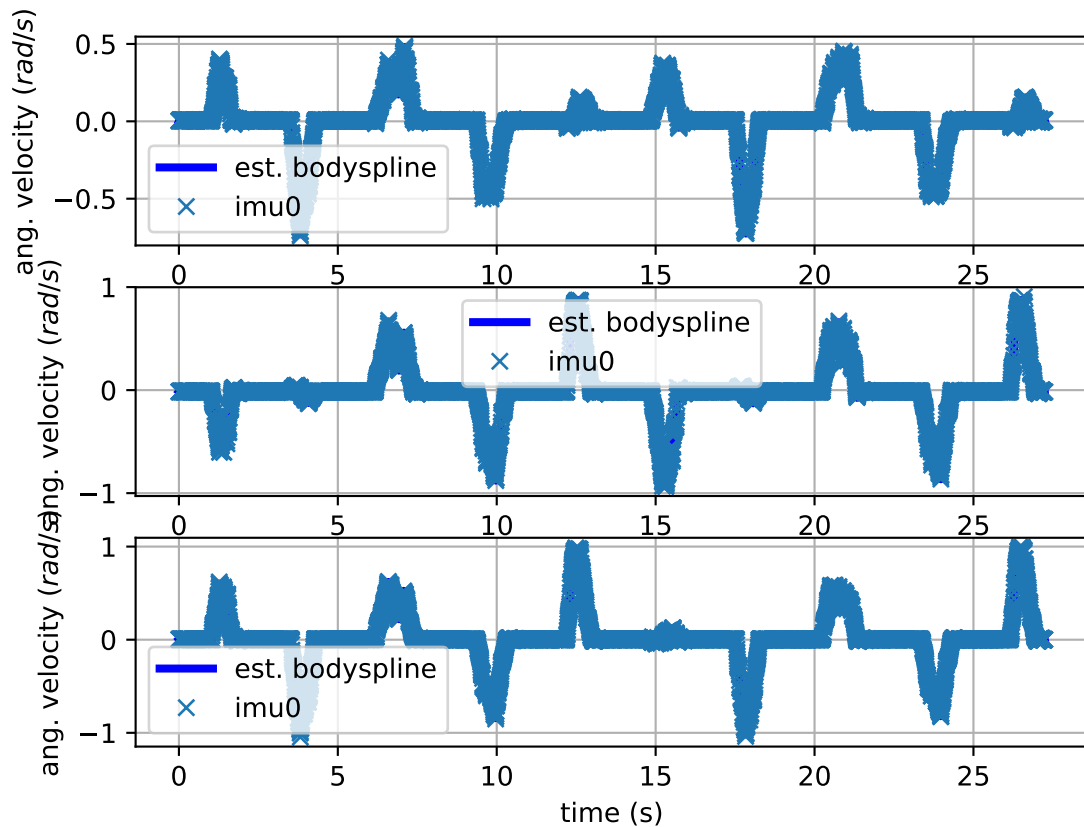Comparison of predicted and measured specific force (imu0 frame)
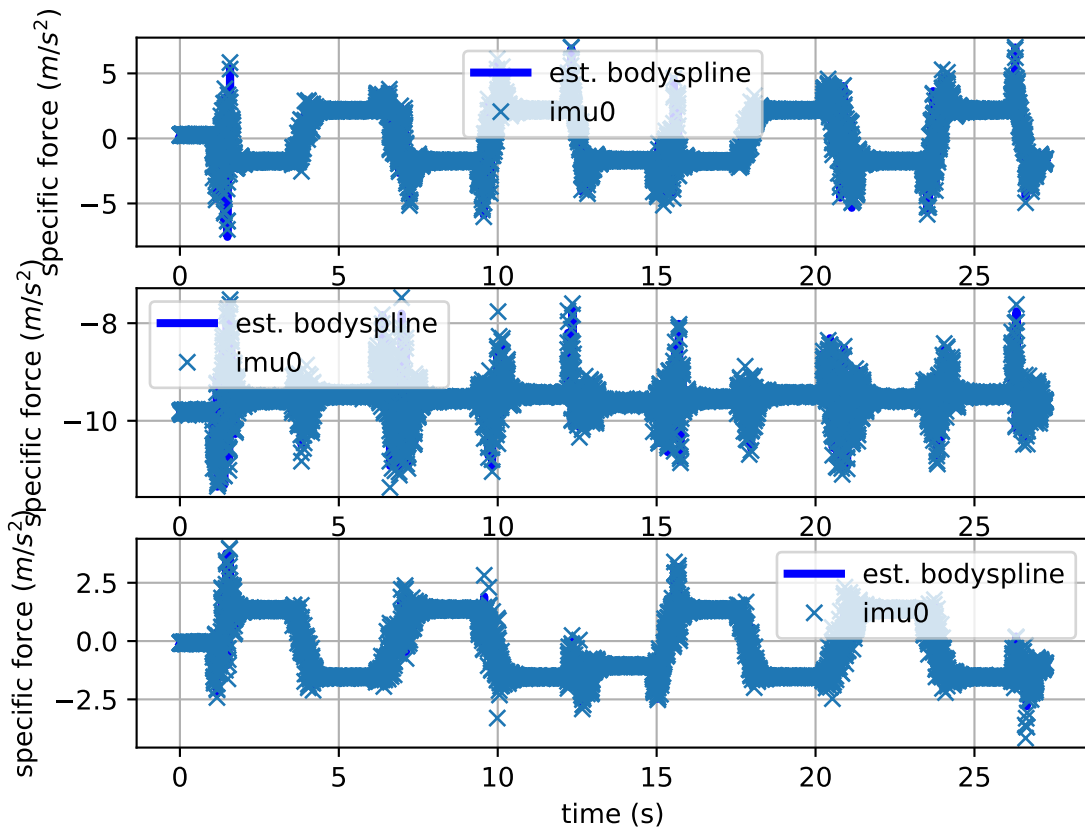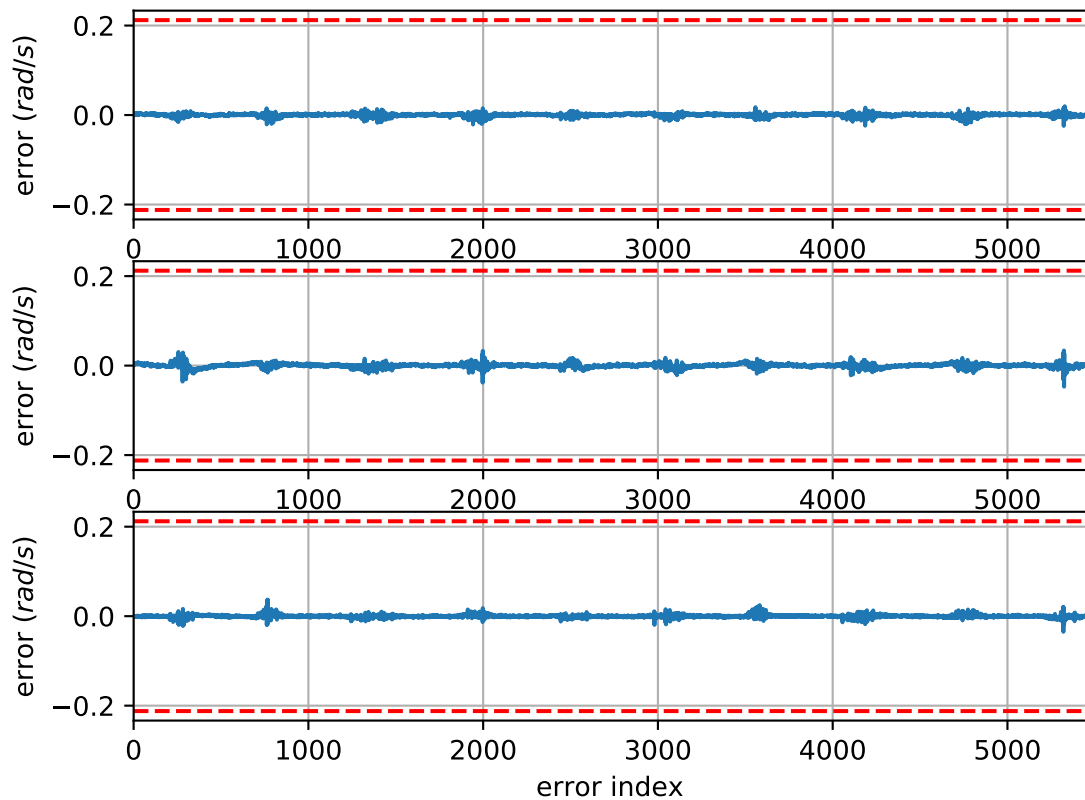
imu0: acceleration error

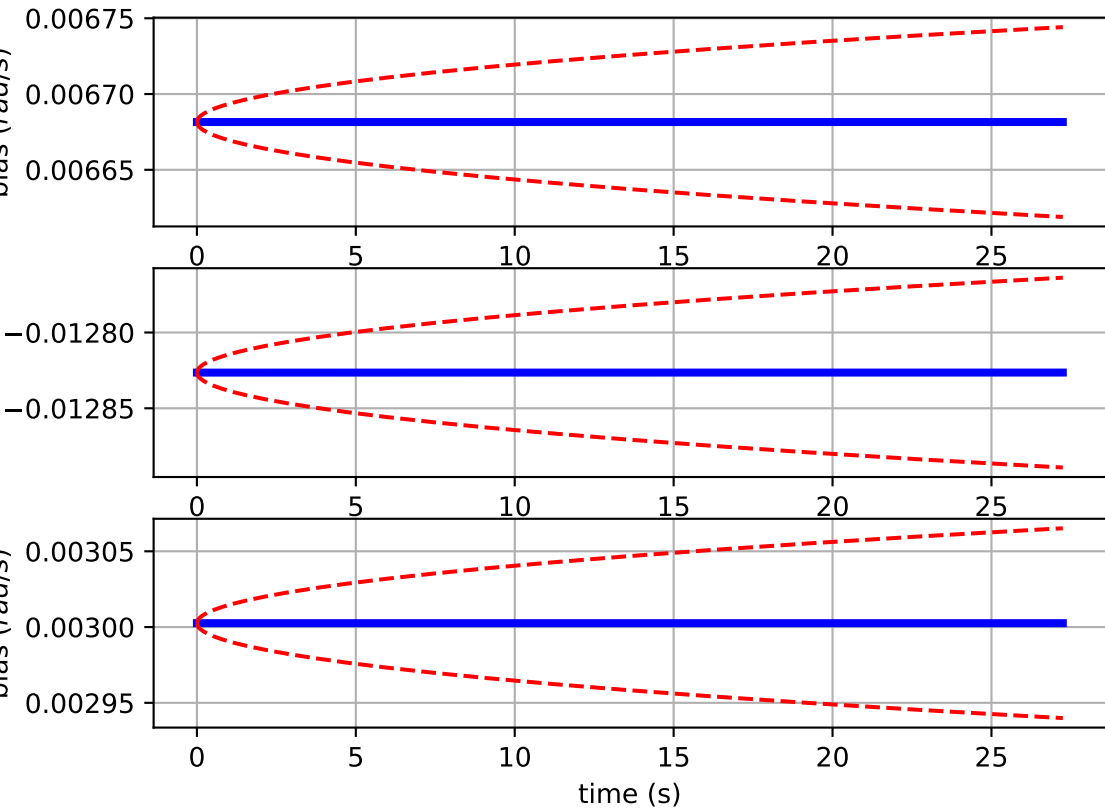imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors