Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.237882793403, median 0.20704159928, std: 0.14984749423
Gyroscope error (imu0):   mean 0.133990039624, median 0.0989186131641, std: 0.108919385857
Accelerometer error (imu0):   mean 0.475209047823, median 0.267036521662, std: 0.685089553542

Residuals

Reprojection error (cam0) [px]:   mean 0.237882793403, median 0.20704159928, std: 0.14984749423
Gyroscope error (imu0) [rad/s]:   mean 0.00947452656295, median 0.00699460221539, std: 0.0077017636342
Accelerometer error (imu0) [m/s^2]: mean 0.0672047080394, median 0.0377646670583, std: 0.0968862938059

Transformation (cam0):

T_ci: (imu0 to cam0):
[[-0.99989865 -0.00867233 0.01129115 0.05501367]
 [-0.01102667 -0.02996205 -0.99949021 0.01308897]
 [0.00900622 -0.99951341 0.02986338 -0.11810204]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[-0.99989865 -0.01102667 0.00900622 0.05621607]
 [-0.00867233 -0.02996205 -0.99951341 -0.11717531]
 [0.01129115 -0.99949021 0.02986338 0.01598806]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
0.00414261421299

Gravity vector in target coords: [m/s^2]
[-0.00731422 -9.52172659 -2.34629327]

Calibration configuration
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cam0

  Camera model: pinhole
  Focal length: [679.5951163793609, 686.2814030050388]
  Principal point: [393.13467146176555, 205.73275622083634]
  Distortion model: equidistant
  Distortion coefficients: [0.4545486629370577, 0.5252236556754005, -4.112514935575864, 6.714651299988109]
  Type: aprilgrid
  Tags:
    Rows: 6
    Cols: 6
    Size: 0.083 [m]
   Spacing 0.0249 [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.]]
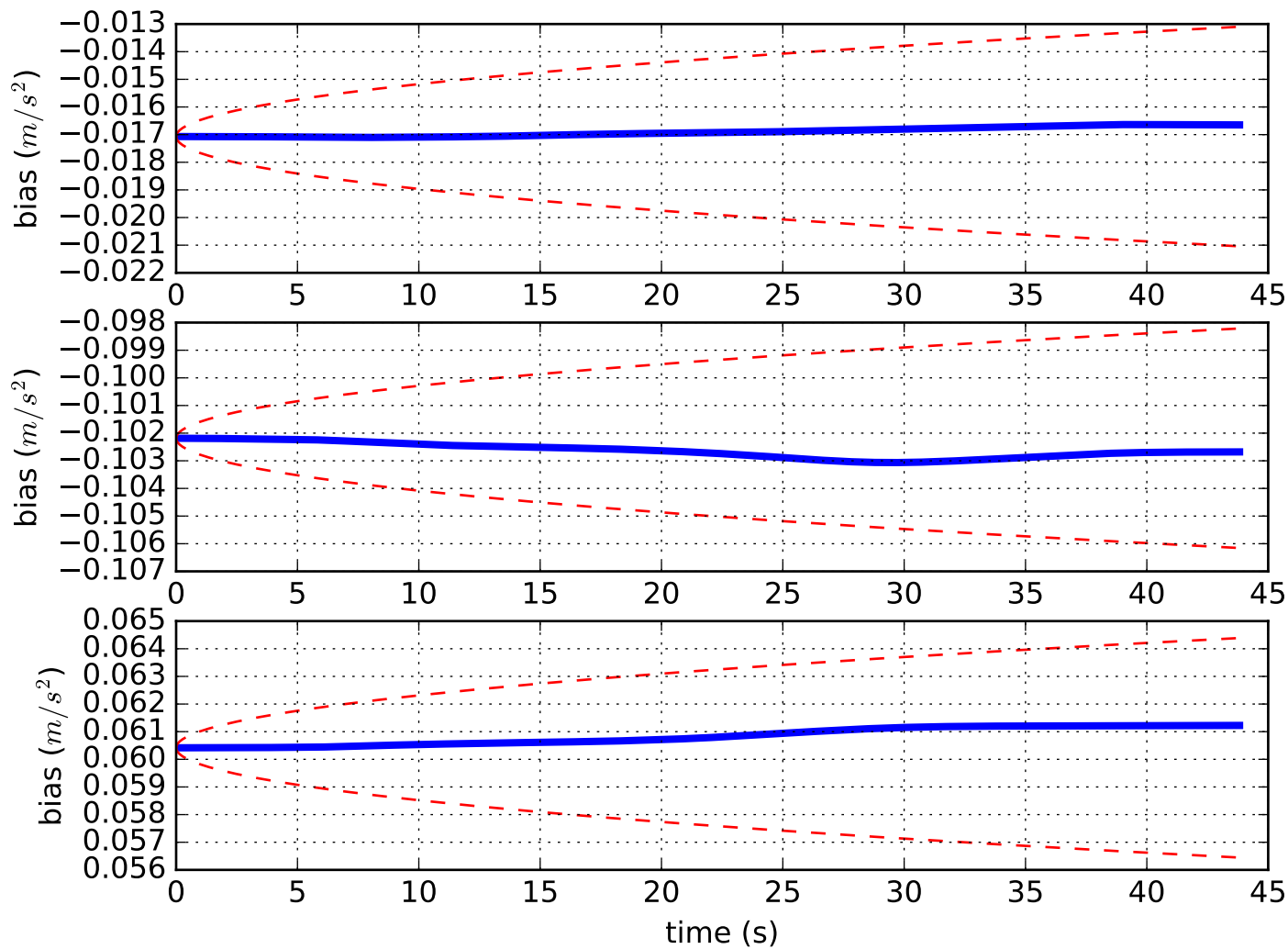 time offset with respect to IMU0: 0.0 [s]

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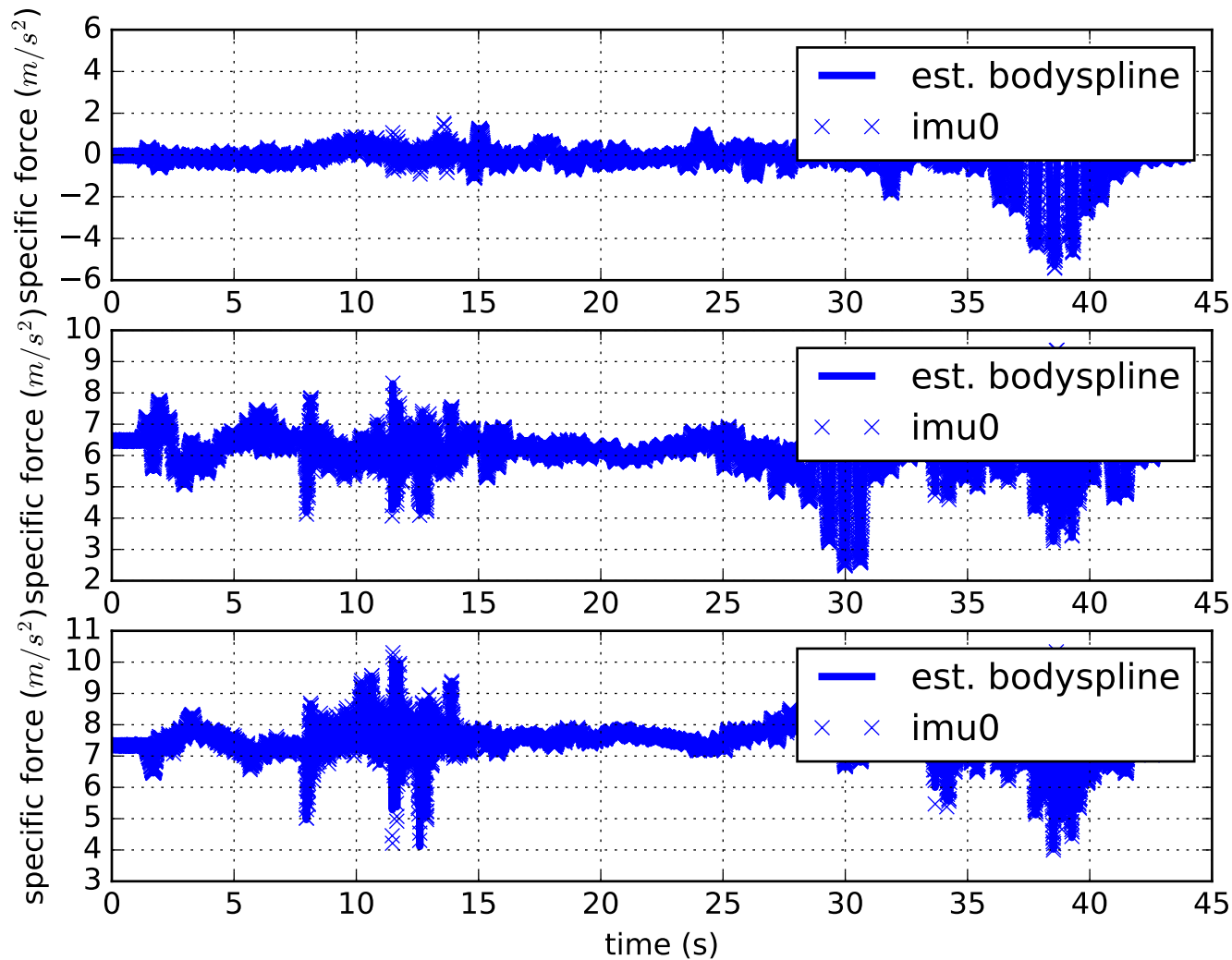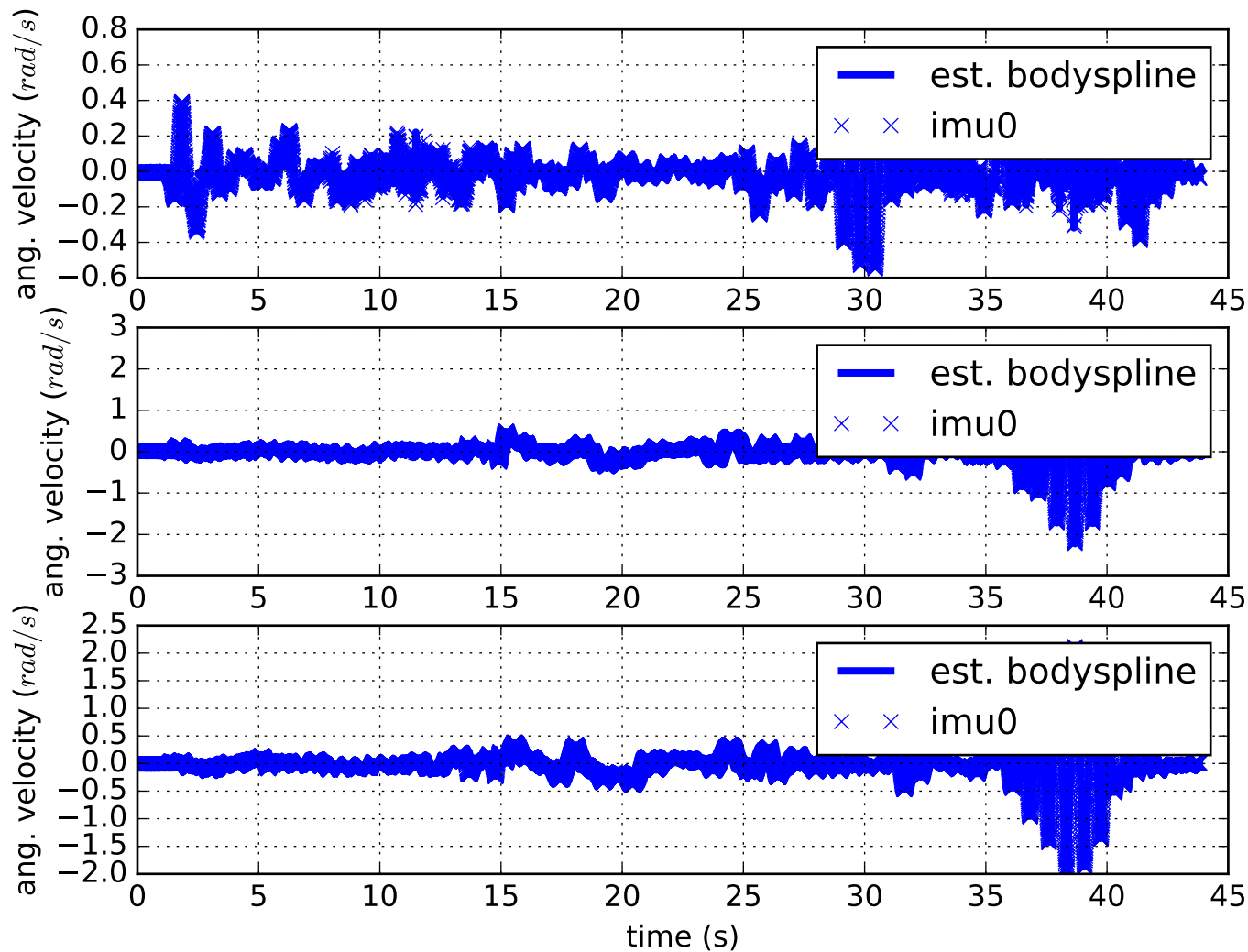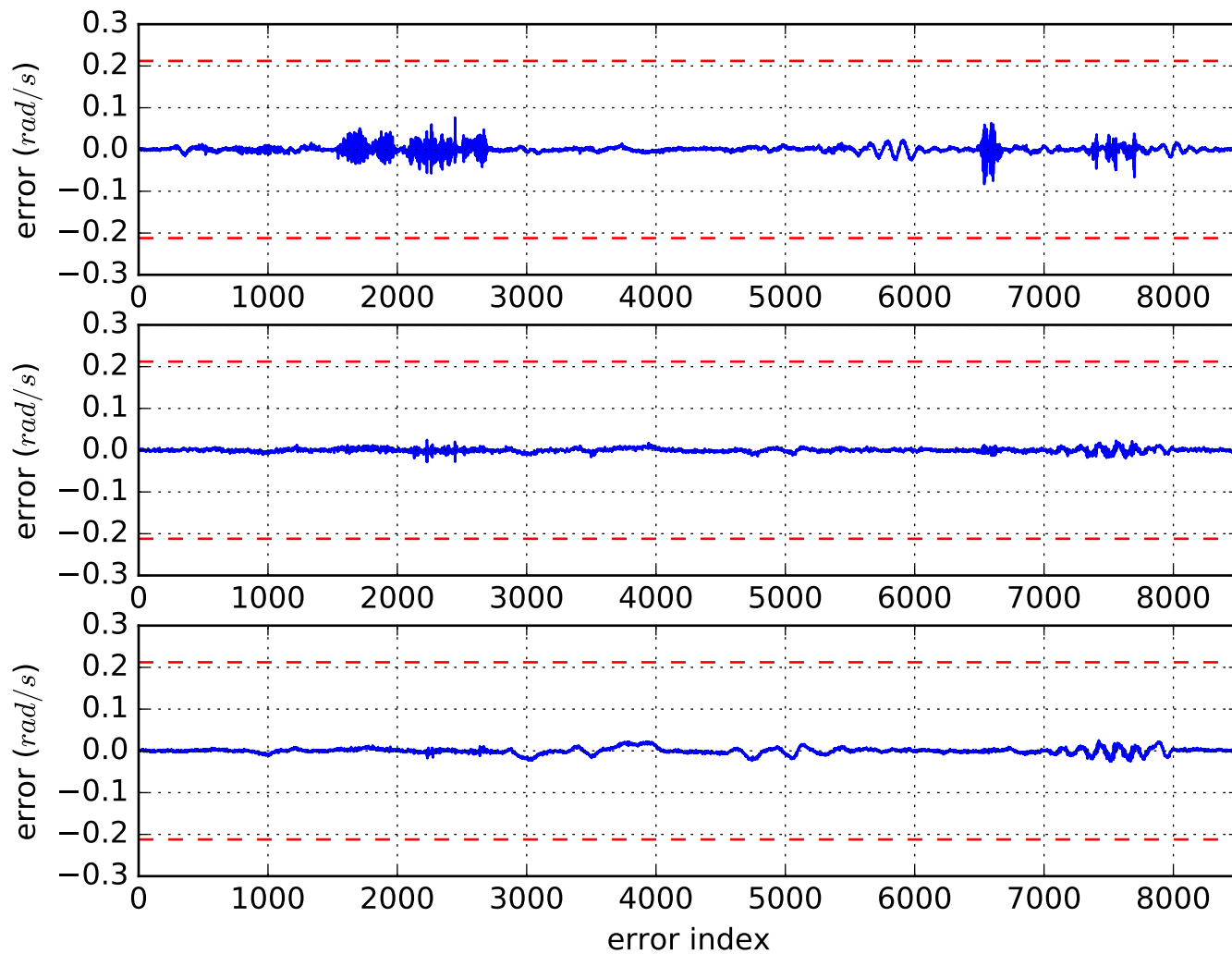
imu0: acceleration error
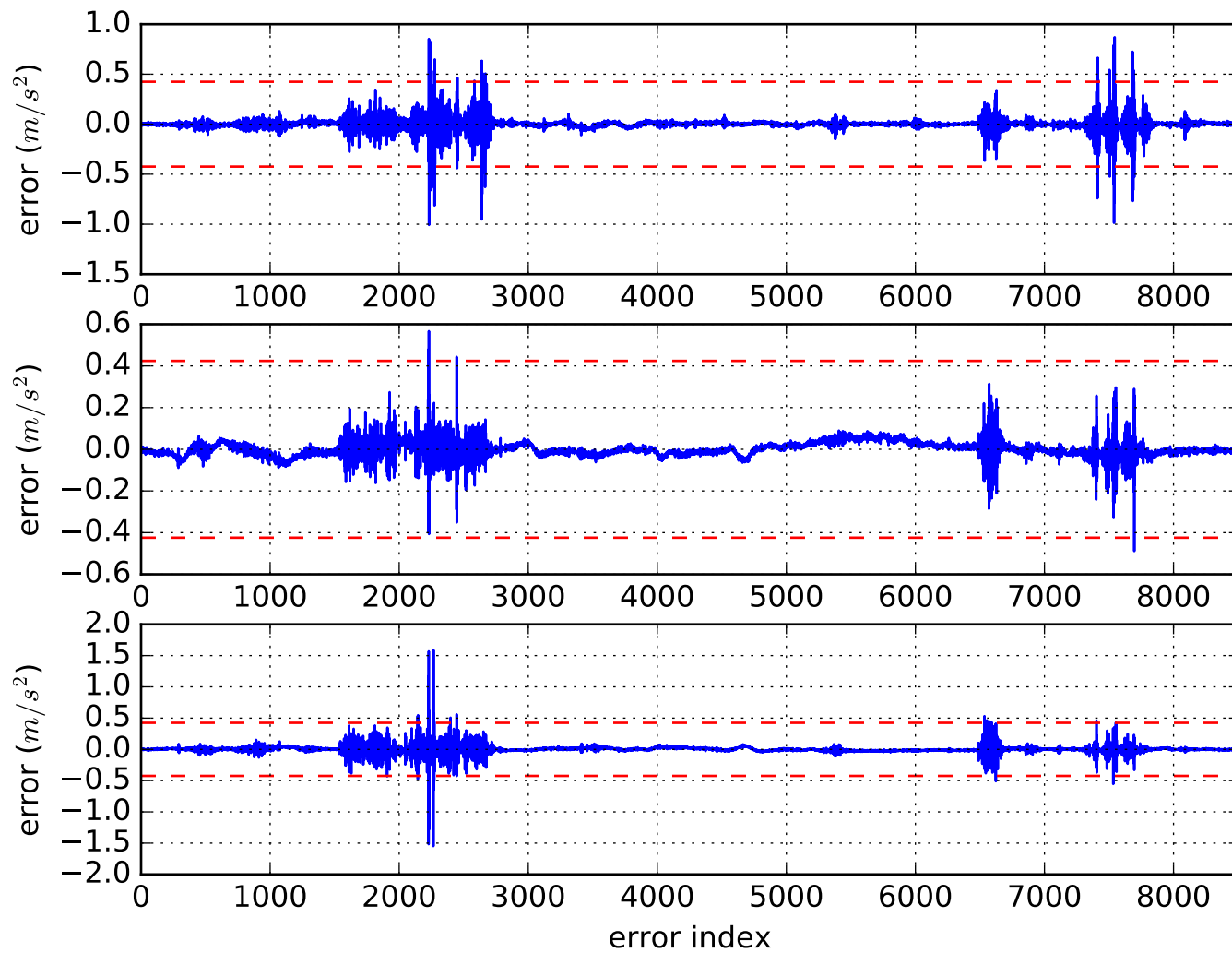
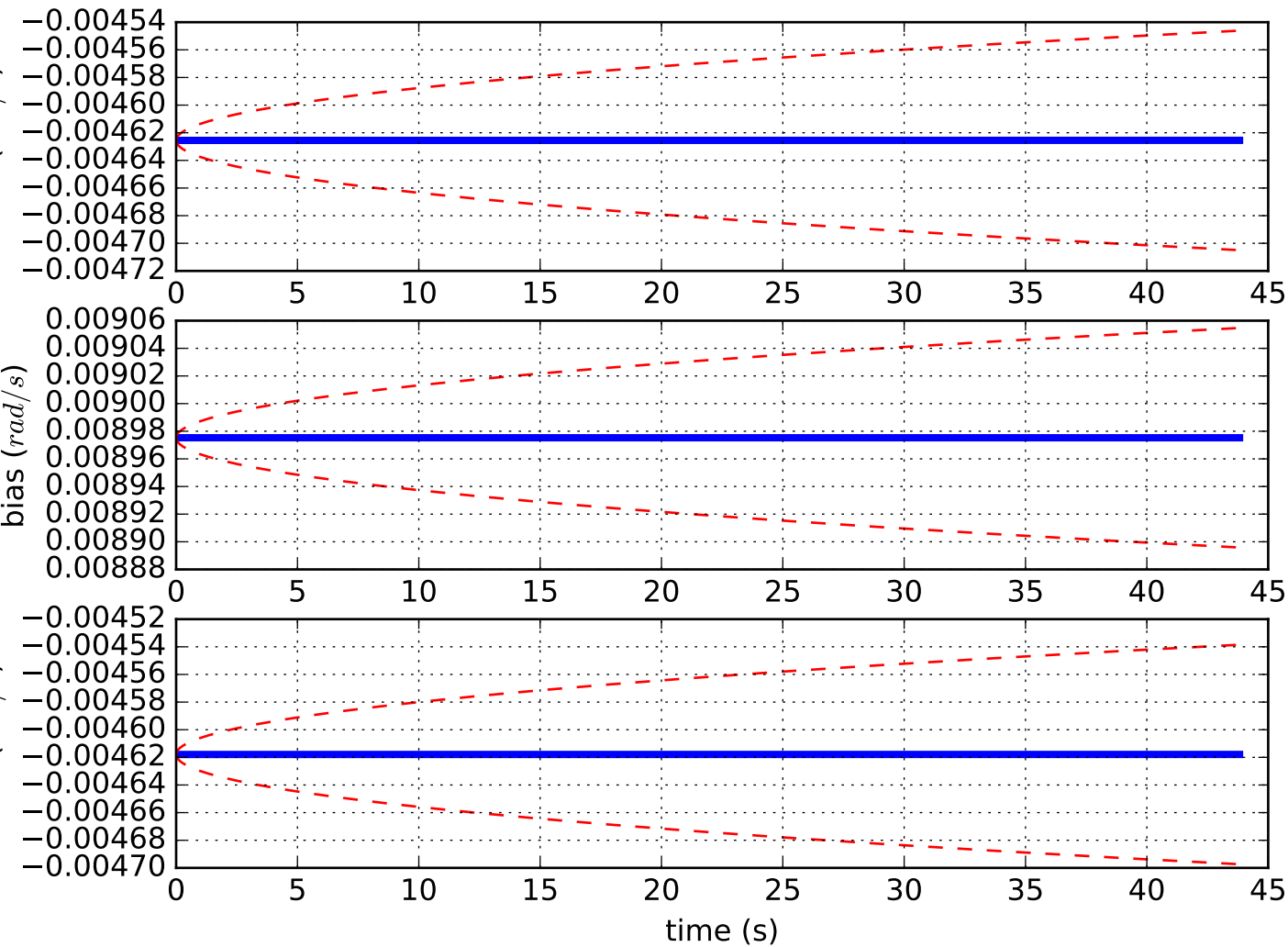imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors