Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 1.91342213567, median 1.66940737774, std: 1.31772463985
Gyroscope error (imu0):   mean 0.000650883369293, median 4.06631188614e-08, std: 0.00461701503366
Accelerometer error (imu0):   mean 0.000233800411951, median 0.000236739104959, std: 1.63477268265e-05

Residuals

Reprojection error (cam0) [px]:   mean 1.91342213567, median 1.66940737774, std: 1.31772463985
Gyroscope error (imu0) [rad/s]:   mean 1.33431090705e-05, median 8.33593936658e-10, std: 9.46488081901e-05
Accelerometer error (imu0) [m/s^2]: mean 7.48161318245e-07, median 7.5756513587e-07, std: 5.23127258447e-08

Transformation (cam0):

T_ci: (imu0 to cam0):
[[-0.0877146 -0.98924242 -0.11707083 0.00037449]
 [-0.47429039 0.14482152 -0.86837512 -0.00003595]
 [0.87598789 -0.02064361 -0.48189113 -0.00240202]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[-0.0877146 -0.47429039 0.87598789 0.00211994]
 [-0.98924242 0.14482152 -0.02064361 0.00032608]
 [-0.11707083 -0.86837512 -0.48189113 -0.00114488]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
0.0

Gravity vector in target coords: [m/s^2]
[0.91648205 -9.50205071 -2.24488658]

Calibration configuration
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cam0

  Camera model: omni
  Focal length: [207.06448, 206.66068]
  Principal point: [324.838, 208.3764]
  Omni xi: 1
  Distortion model: radtan
  Distortion coefficients: [1.2828, 0.0108, -0.02, 0.0167]
  Type: aprilgrid
  Tags:
    Rows: 6
    Cols: 6
    Size: 0.067 [m]
   Spacing 0.0199995 [m]

IMU configuration
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IMU0:

  Model: calibrated
  Update rate: 25
  Accelerometer:
    Noise density: 0.00064
    Noise density (discrete): 0.0032
    Random walk: 8.86e-07
  Gyroscope:
    Noise density: 0.0041
    Noise density (discrete): 0.0205
    Random walk: 5.7e-07
  T_i_b
    [[1. 0. 0. 0.]
     [0. 1. 0. 0.]
     [0. 0. 1. 0.]
     [0. 0. 0. 1.]]
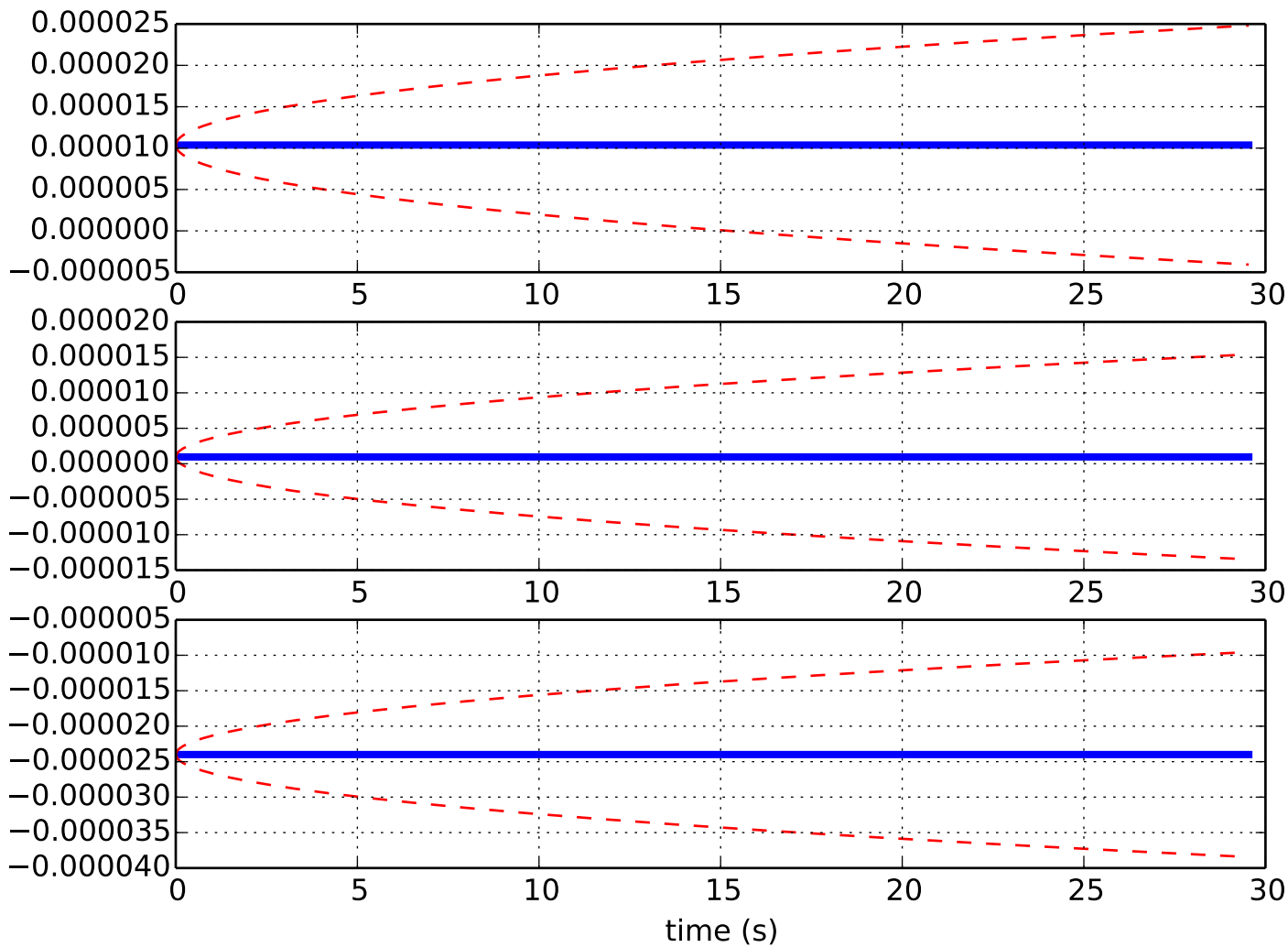 time offset with respect to IMU0: 0.0 [s]

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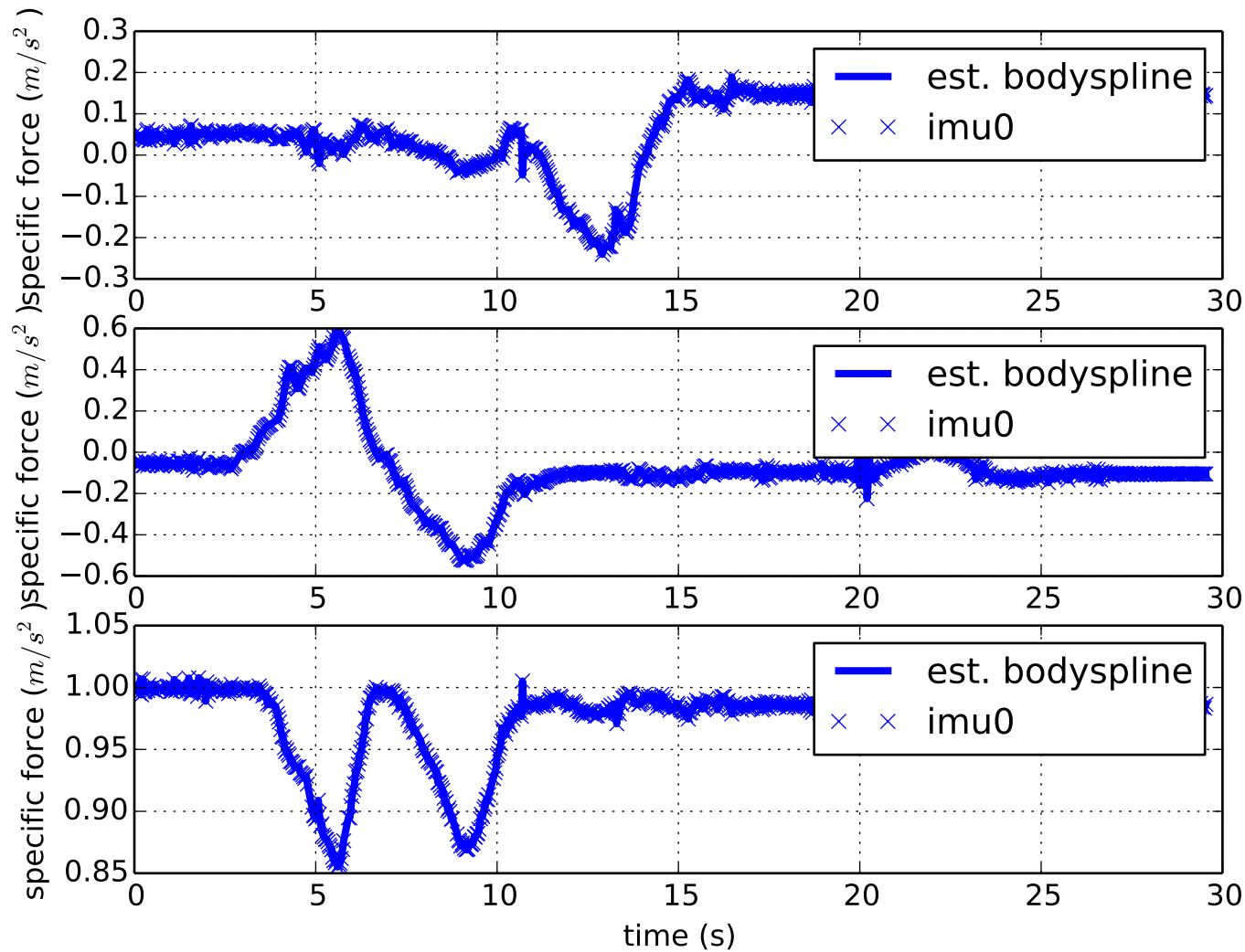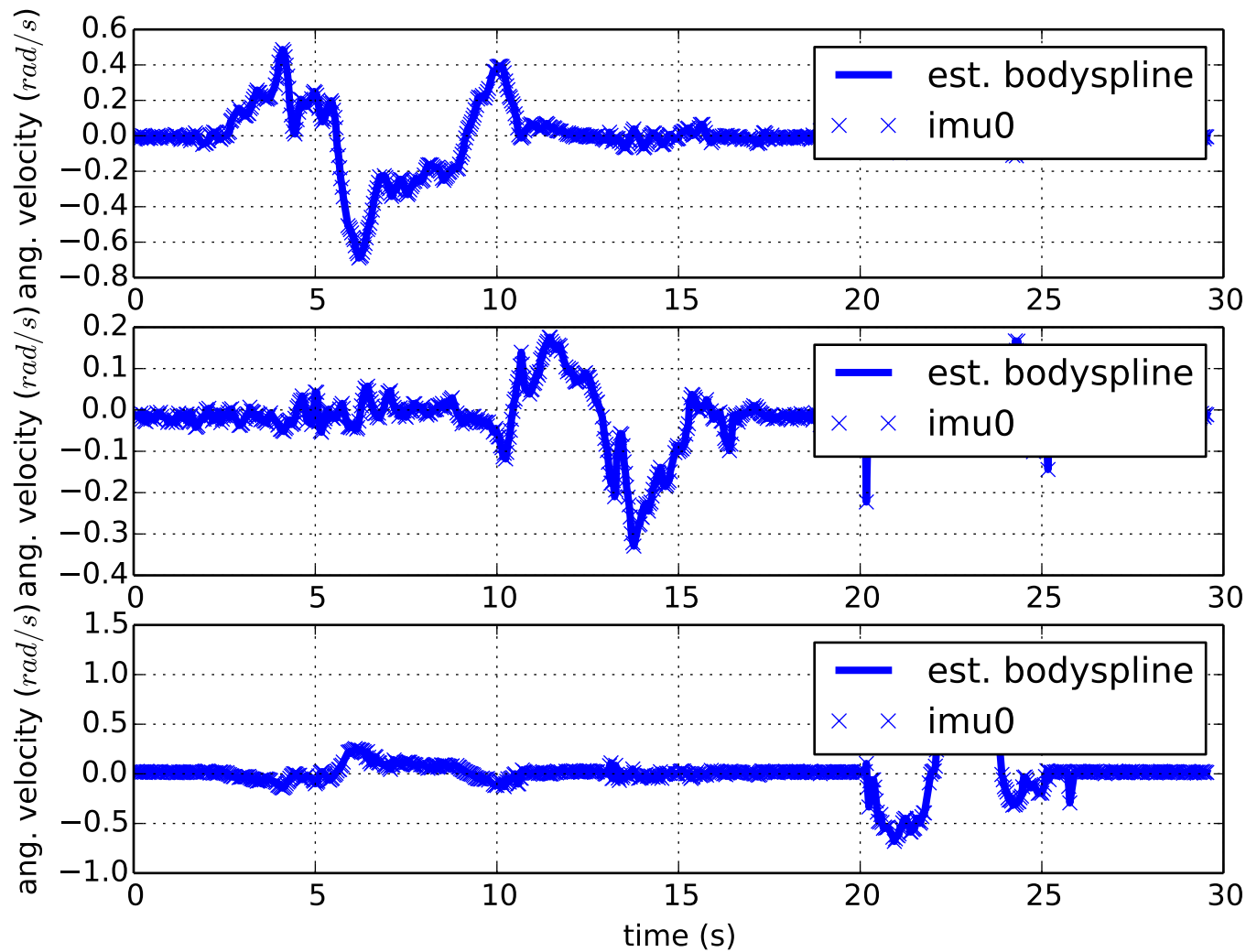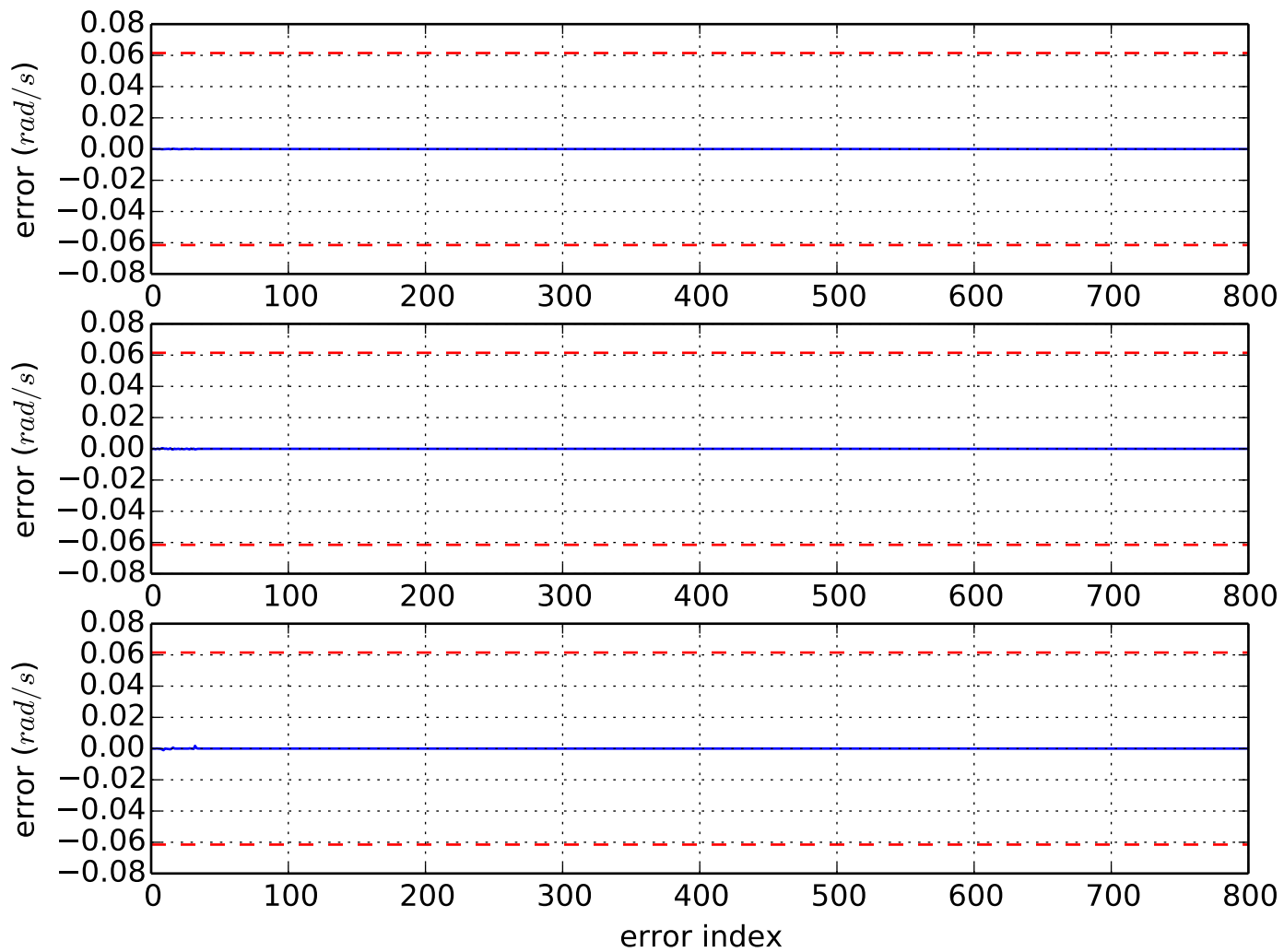
imu0: acceleration error
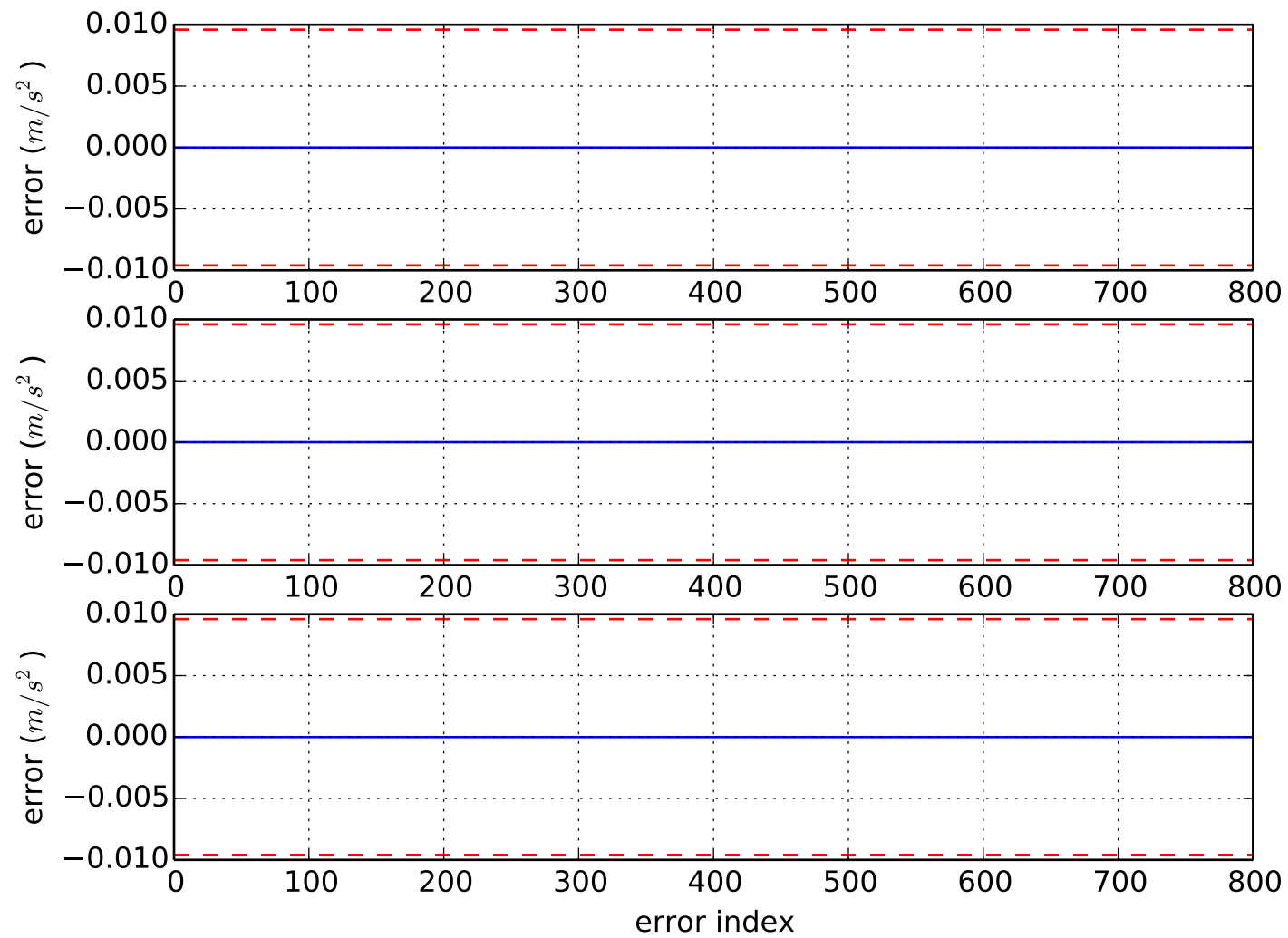
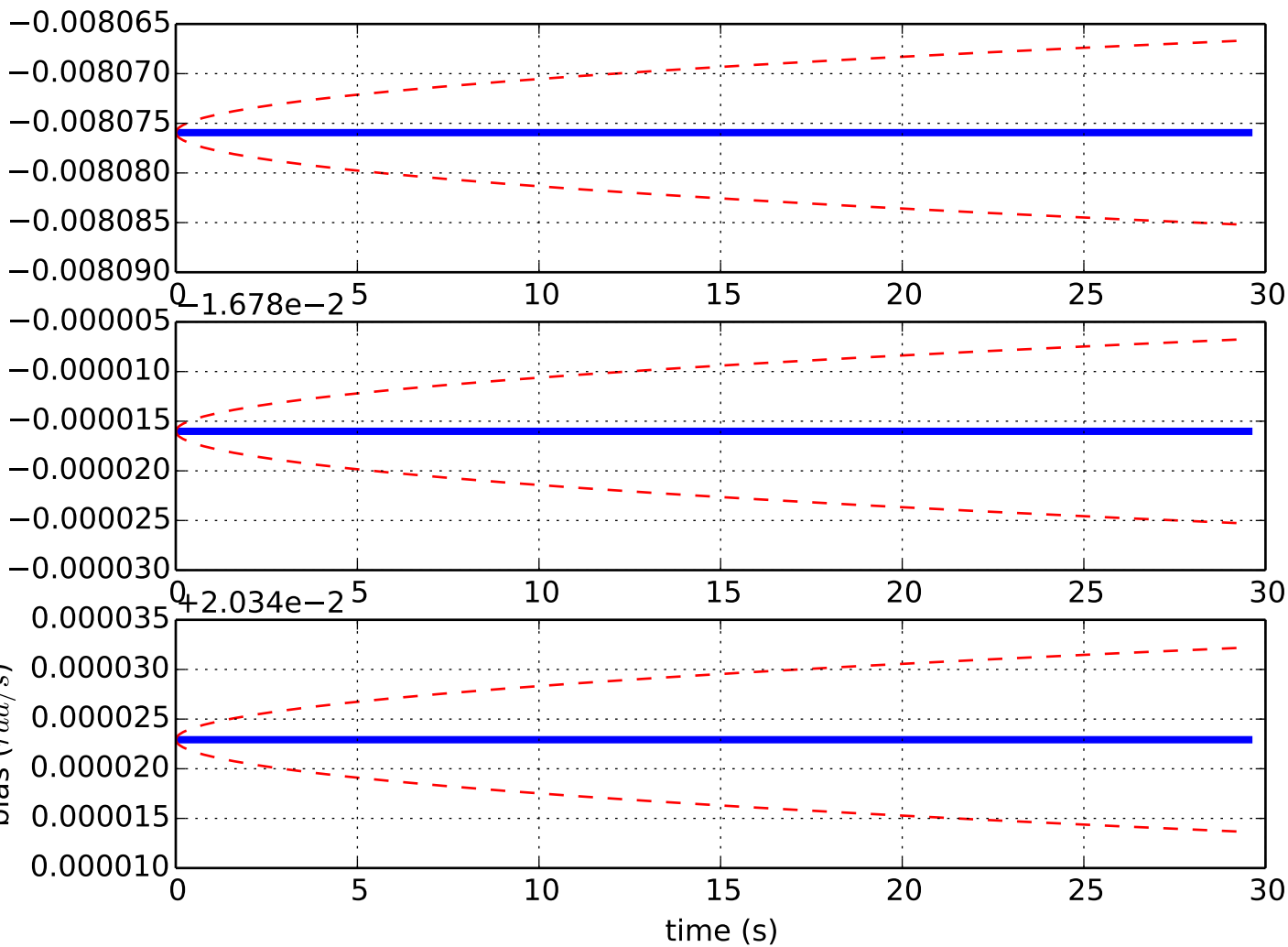imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors