Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.613216394946, median 0.535818073895, std: 0.402676615575
Reprojection error (cam1):   mean 0.526697168603, median 0.421670035715, std: 0.381633474244
Gyroscope error (imu0):   mean 0.0245157490215, median 0.0209368740449, std: 0.0162225874609
Accelerometer error (imu0):   mean 0.0649355295181, median 0.051133099777, std: 0.061104478509

Residuals

Reprojection error (cam0) [px]:   mean 0.613216394946, median 0.535818073895, std: 0.402676615575
Reprojection error (cam1) [px]:   mean 0.526697168603, median 0.421670035715, std: 0.381633474244
Gyroscope error (imu0) [rad/s]:   mean 0.0274094406657, median 0.0234081368004, std: 0.018137404166
Accelerometer error (imu0) [m/s^2]: mean 0.145200258157, median 0.114337087002, std: 0.13663376767

Transformation (cam0):

T_ci: (imu0 to cam0):
[[-0.02822879 -0.99960149 0.00001218 0.02172388]
 [0.01440125 -0.00041887 -0.99989621 -0.00006605]
 [0.99949774 -0.02822568 0.01440734 -0.00048818]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[-0.02822879 0.01440125 0.99949774 0.00110212]
 [-0.99960149 -0.00041887 -0.02822568 0.02170142]
 [0.00001218 -0.99989621 0.01440734 -0.00005928]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
-0.0166845720919

Transformation (cam1):

T_ci: (imu0 to cam1):

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  [ 0.          0.          0.          1.         ]]

T_ic: (cam1 to imu0):
[[-0.01182306  0.01155299  0.99986336 -0.00029028]
 [-0.99987014  0.01081377 -0.01194809 -0.05790695]
 [-0.01095033 -0.99987479  0.01142364 -0.0001919 ]
 [ 0.          0.          0.          1.         ]]

timeshift cam1 to imu0: [s] (t_imu = t_cam + shift)
-0.0165914312471

Baselines:
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Baseline (cam0 to cam1):
[[ 0.9998053   0.01119774  0.01624713 -0.07961594]
 [-0.01114776  0.99993286 -0.00316357  0.00074435]
 [-0.01628147  0.00298183  0.999863    0.00044255]
 [ 0.          0.          0.          1.         ]]
baseline norm:  0.0796206523673 [m]


Gravity vector in target coords: [m/s^2]
[ 0.078163  -9.27130891 -3.1945492 ]


Calibration configuration
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cam0
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  Camera model: pinhole
  Focal length: [278.66723066149086, 278.48991409740296]
  Principal point: [319.75221200593535, 241.96858910358173]
  Distortion model: equidistant
  Distortion coefficients: [-0.013721808247486035, 0.020727425669427896, -0.012786476702685545, 0.00
  Type: aprilgrid
  Tags:
```

Spacing 0.015 [m]

cam1

  Camera model: pinhole
  Focal length: [277.61640629770613, 277.63749695723294]
  Principal point: [314.8944703346039, 236.04310050462587]
  Distortion model: equidistant
  Distortion coefficients: [-0.008456929295619607, 0.011407590938612062, -0.006951788325762078, 0.00
  Type: aprilgrid
  Tags:
    Rows: 4
    Cols: 5
    Size: 0.075 [m]
    Spacing 0.015 [m]

IMU configuration
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IMU0:

  Model: calibrated
  Update rate: 500.0
  Accelerometer:
    Noise density: 0.1
    Noise density (discrete): 2.2360679775
    Random walk: 0.002
  Gyroscope:
    Noise density: 0.05
    Noise density (discrete): 1.11803398875
    Random walk: 4e-05
  T_i_b
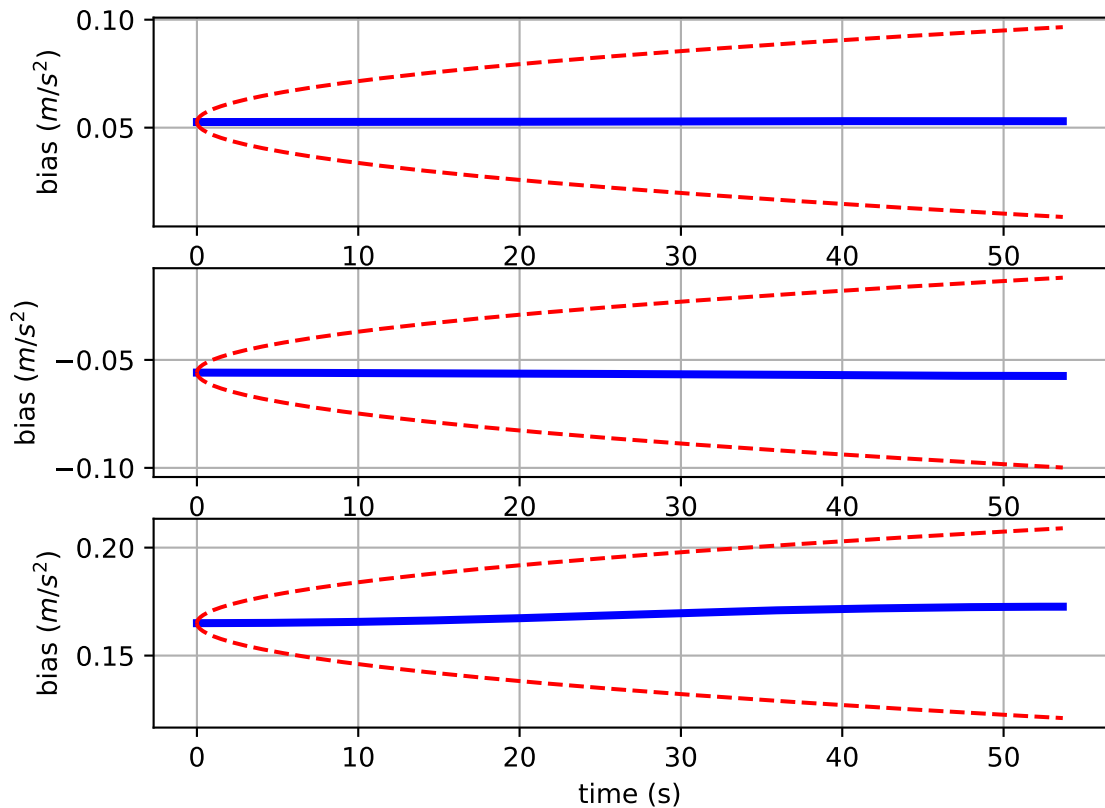   [[1. 0. 0. 0.]
     [0. 1. 0. 0.]

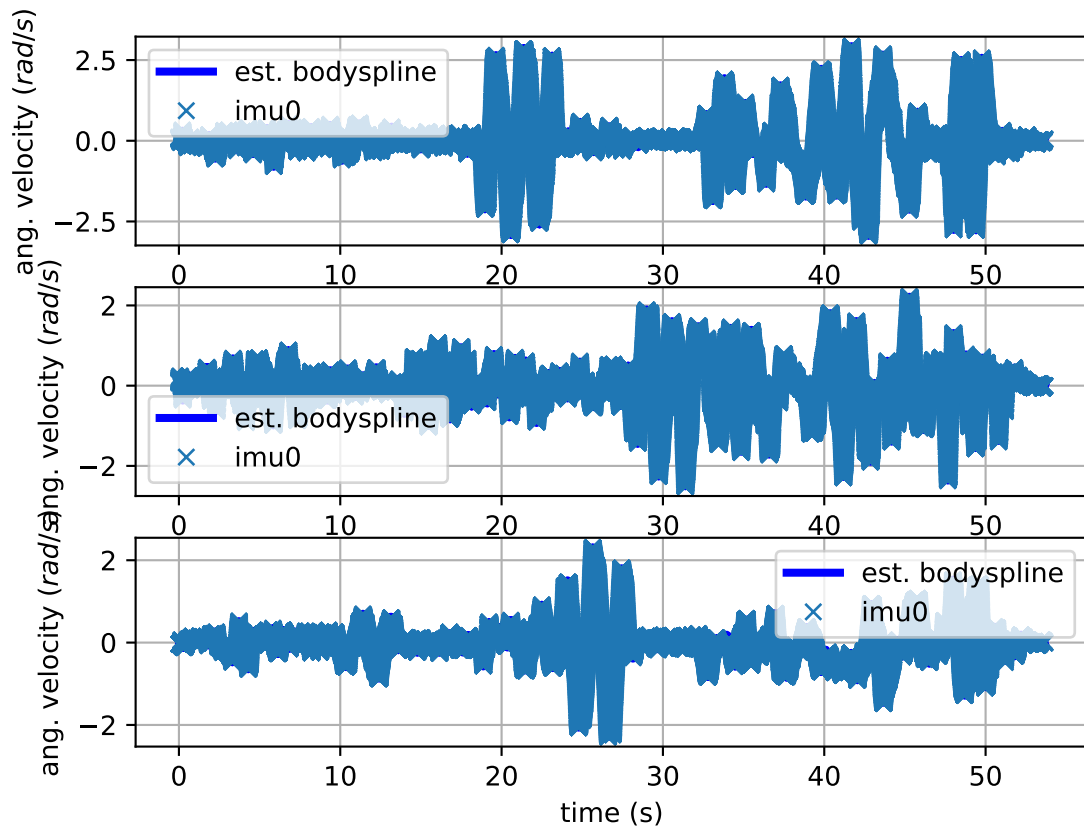Comparison of predicted and measured specific force (imu0 frame)
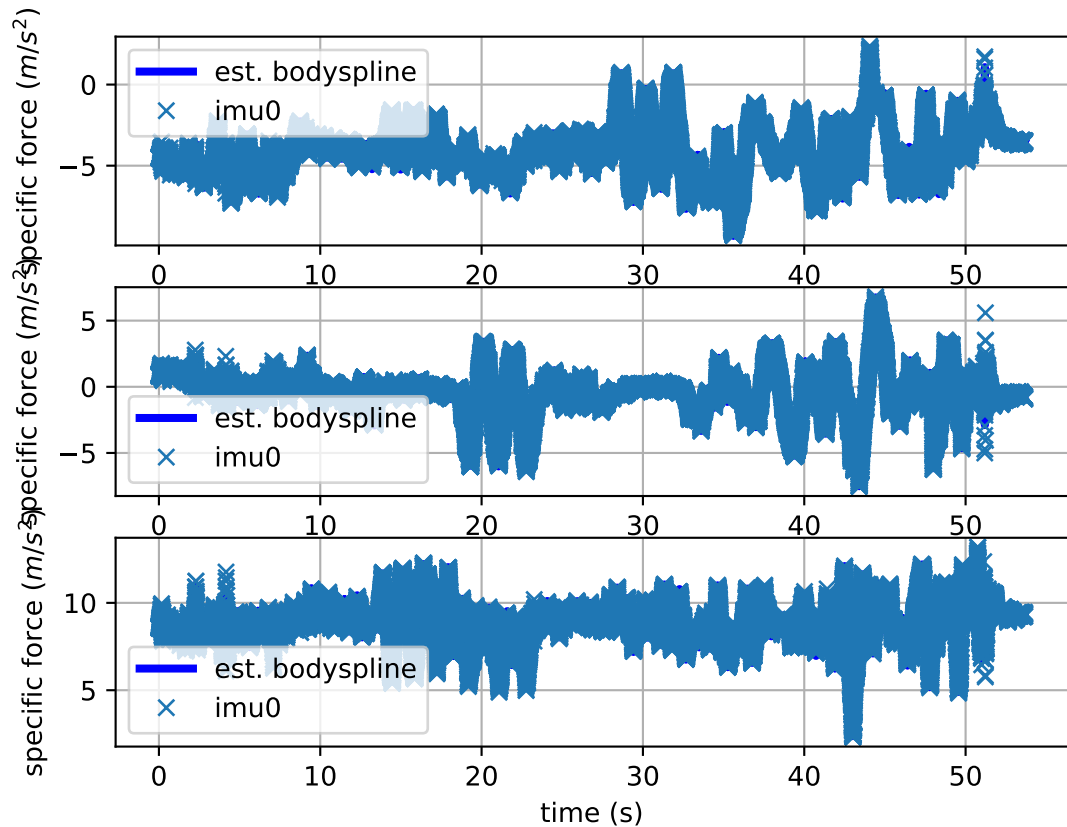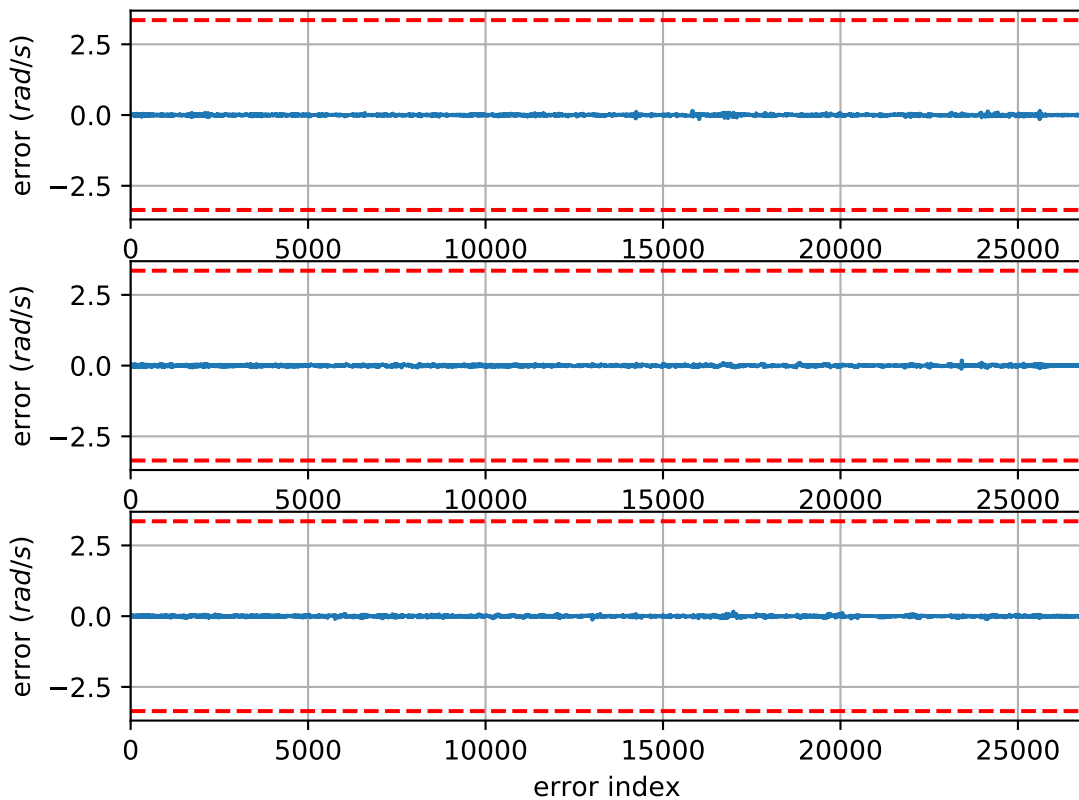
imu0: acceleration error
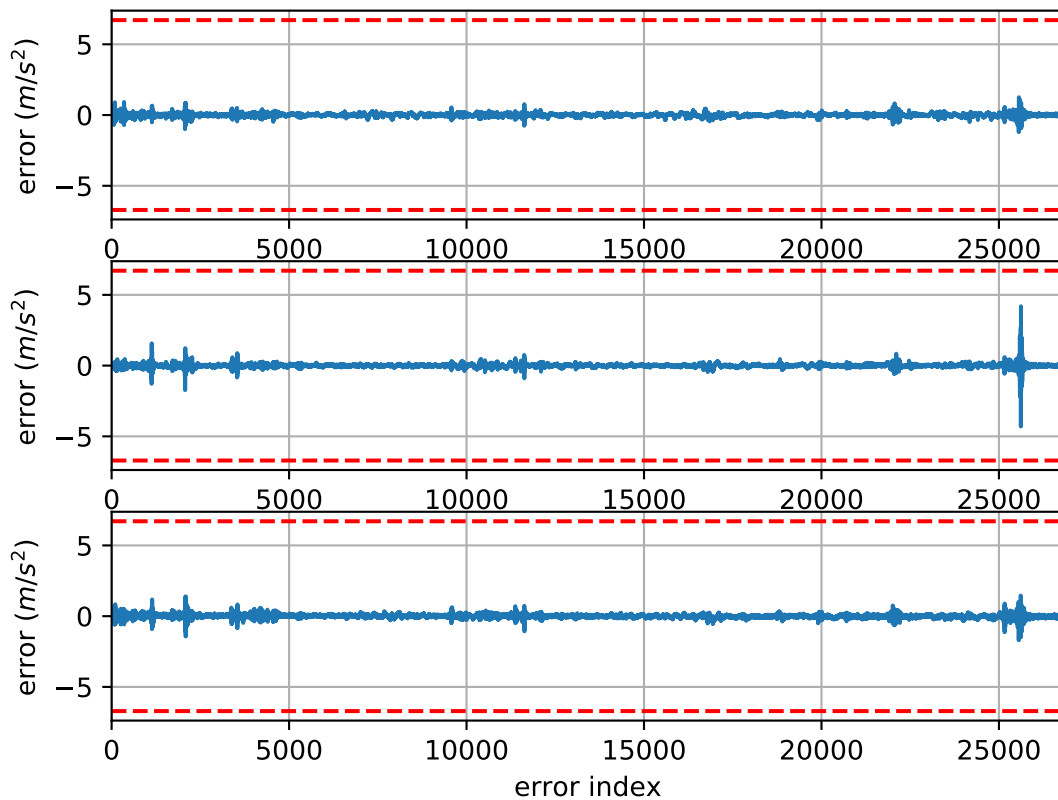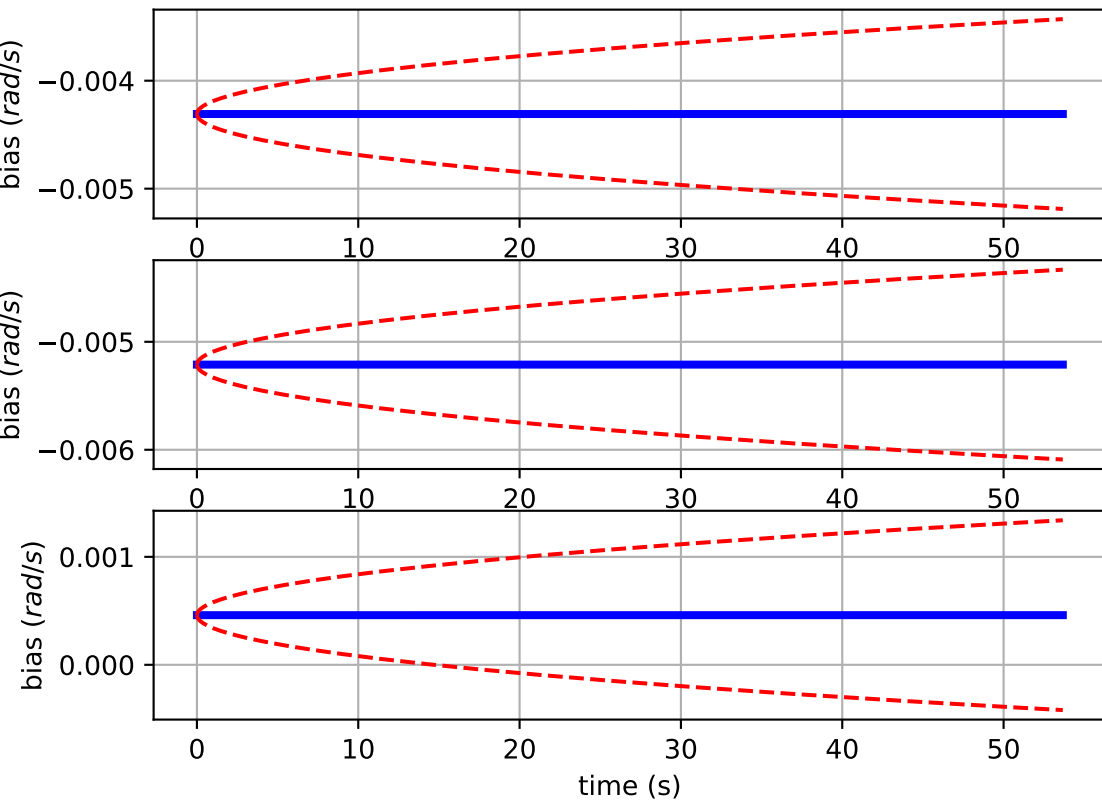
imu0: estimated accelerometer bias (imu frame)

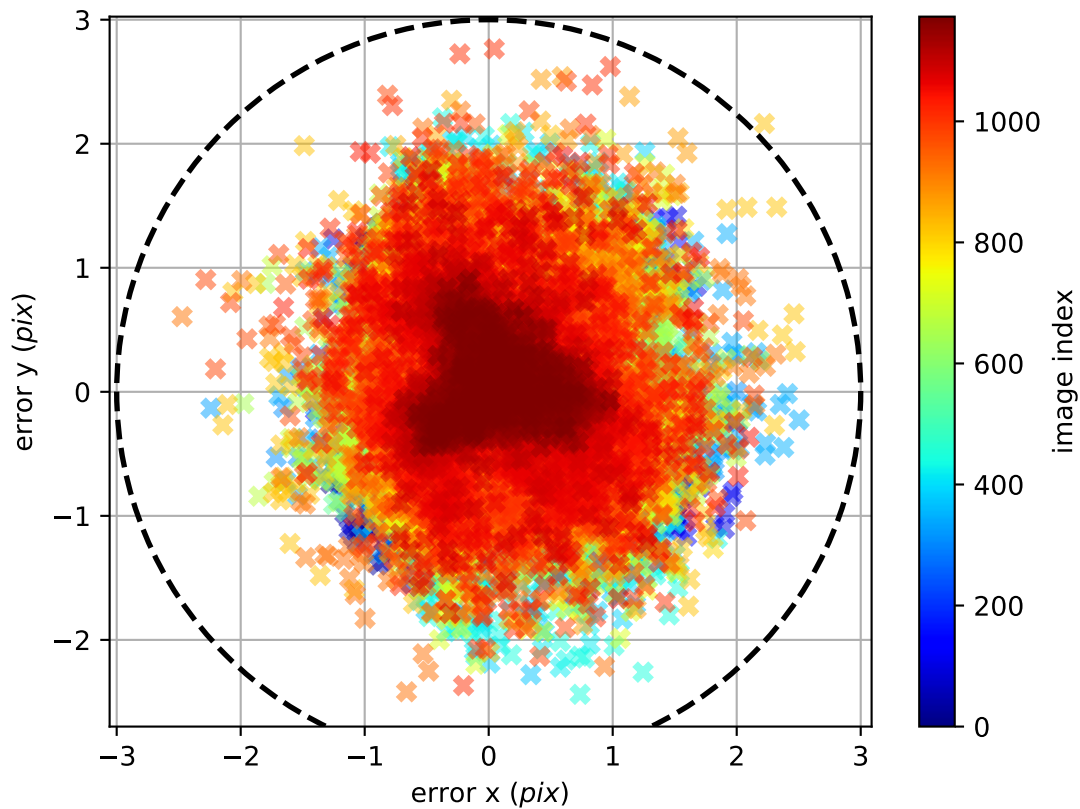Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors

cam1: reprojection errors