Calibration results
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Normalized Residuals

Reprojection error (cam0):   mean 0.3755238505512289, median 0.2997213786041404, std: 0.30331684307438944
Gyroscope error (imu0):   mean 0.7261512593220939, median 0.5718563746556441, std: 0.6196970671783322
Accelerometer error (imu0):   mean 0.8899830322681148, median 0.7031341375941444, std: 0.7131848179788016

Residuals

Reprojection error (cam0) [px]:   mean 0.3755238505512289, median 0.2997213786041404, std: 0.30331684307438944
Gyroscope error (imu0) [rad/s]:   mean 0.0031308937950355435, median 0.0024656317152604596, std:
0.00267190296446179
Accelerometer error (imu0) [m/s^2]: mean 0.24108815476210246, median 0.1904725209769461, std:
0.19319515713986865

Transformation (cam0):

T_ci: (imu0 to cam0):
[[0.99998527 0.00476288 0.00260457 0.05723909]
 [0.00267531 -0.01490535 -0.99988533 -0.03239169]
 [-0.00472351 0.99987757 -0.01491787 -0.06708284]
 [0.   0.   0.   1.   ]]

T_ic: (cam0 to imu0):
[[0.99998527 0.00267531 -0.00472351 -0.05746845]
 [0.00476288 -0.01490535 0.99987757 0.06631919]
 [0.00260457 -0.99988533 -0.01491787 -0.03353779]
 [0.   0.   0.   1.   ]]

timeshift cam0 to imu0: [s] (t_imu = t_cam + shift)
-0.00469846572031349

Gravity vector in target coords: [m/s^2]
[-0.00365655 -9.7294634 -1.22717212]

Calibration configuration
=========================

cam0

Camera model: pinhole
Focal length: [397.5140865834166, 397.0636155168975]
Principal point: [324.6509024299695, 239.43461882257037]
Distortion model: radtan
Distortion coefficients: [-0.341501522923929, 0.10230247731969135, -0.00030846227394207266, 0.0005389293391860201]
Type: aprilgrid
Tags:
Rows: 6
Cols: 6
Size: 0.088 [m]
Spacing 0.026399999999999996 [m]

IMU configuration
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IMU0:

Model: calibrated
Update rate: 100
Accelerometer:
Noise density: 0.027089073164427782
Noise density (discrete): 0.2708907316442778
Random walk: 0.0026405437265548015
Gyroscope:
Noise density: 0.0004311627577370619
Noise density (discrete): 0.0043116275773706185
Random walk: 5.5971879319209416e-05

```
T_ib (imu0 to imu0)
[[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]
```
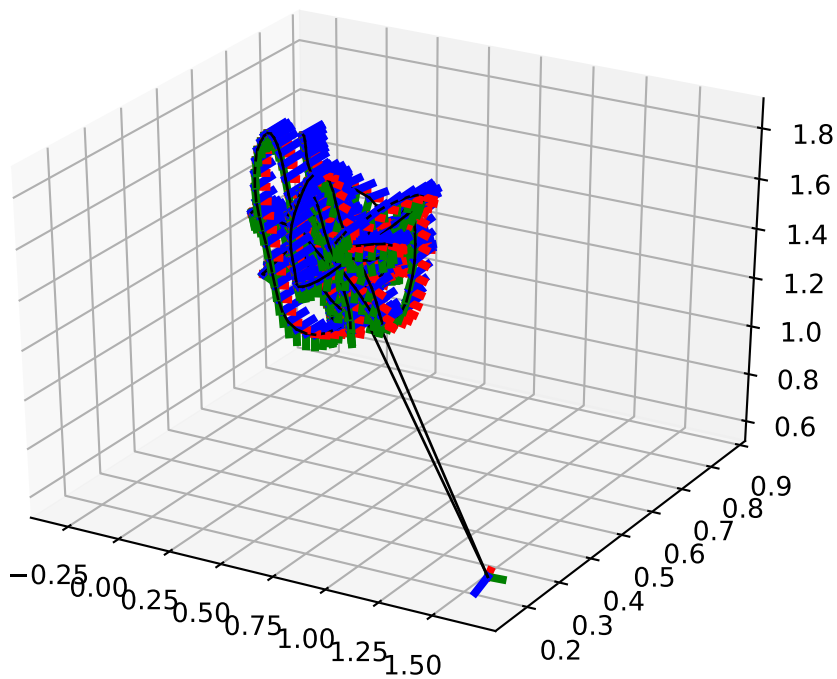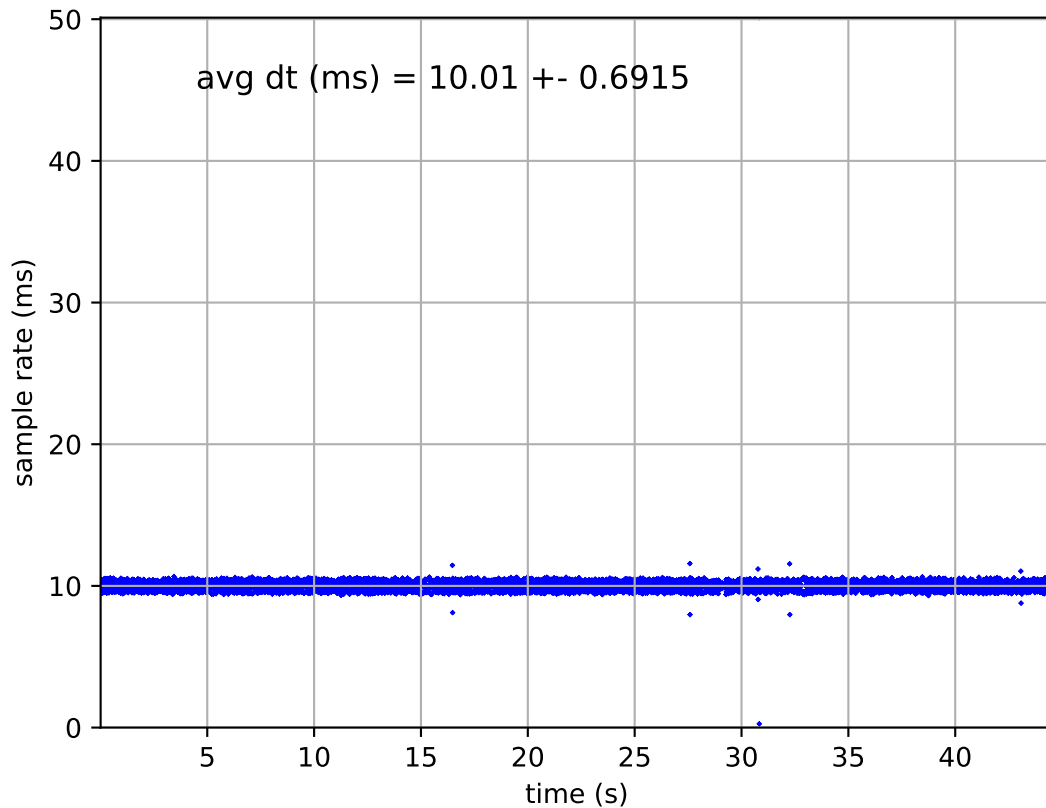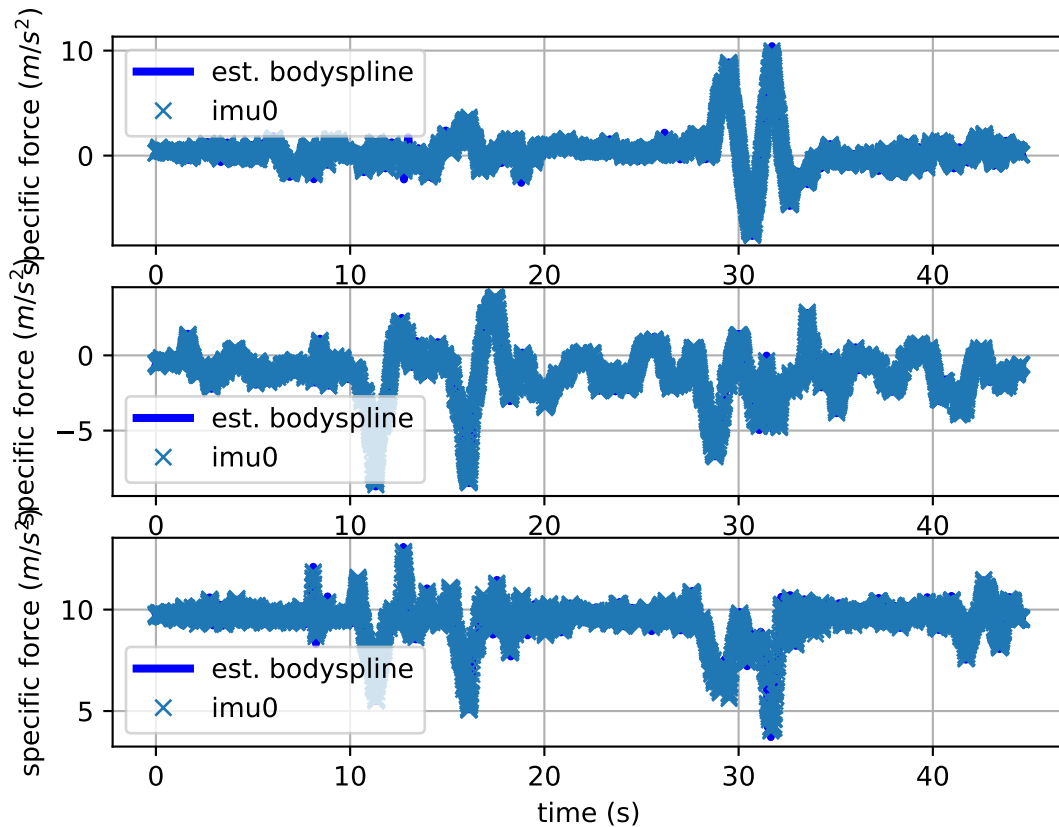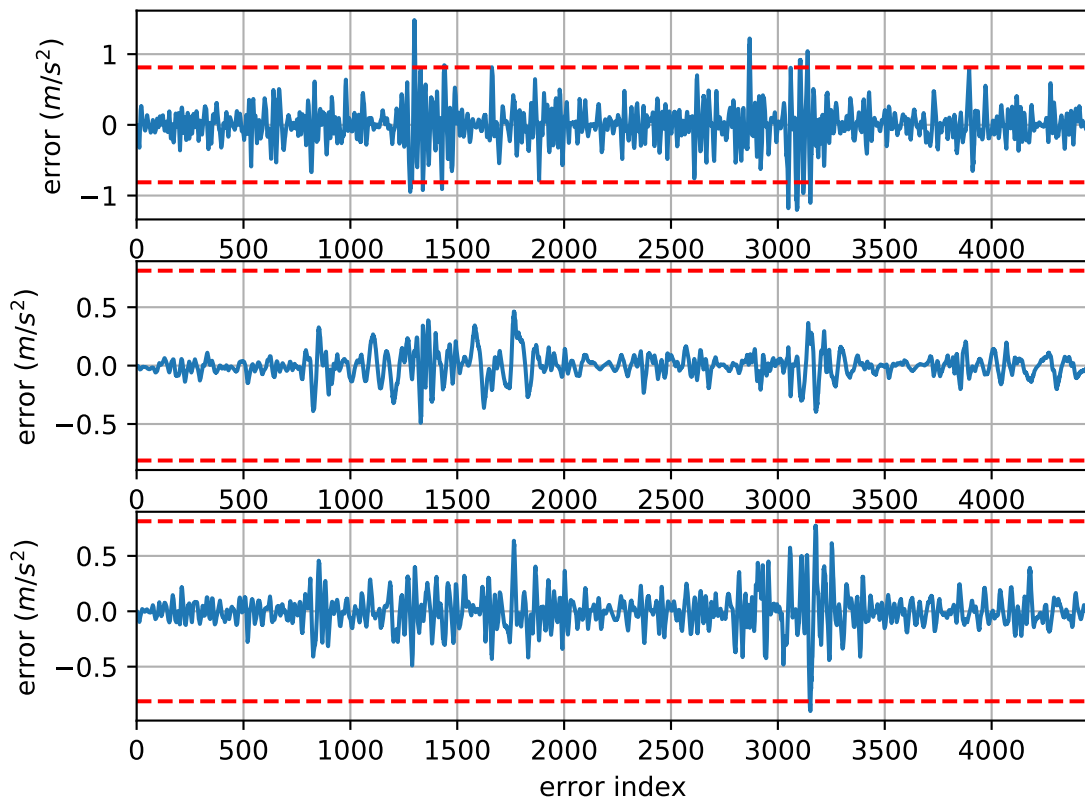
imu0: estimated poses

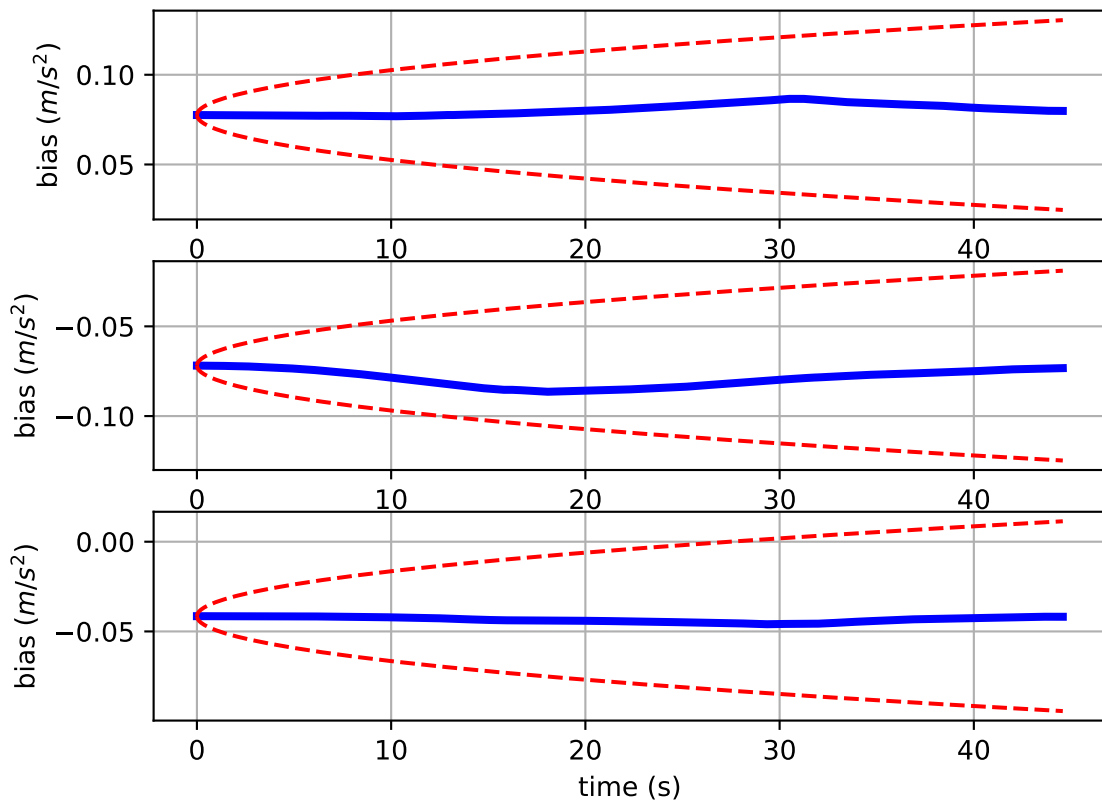imu0: sample inertial rate

avg dt (ms) = 10.01 +- 0.6915

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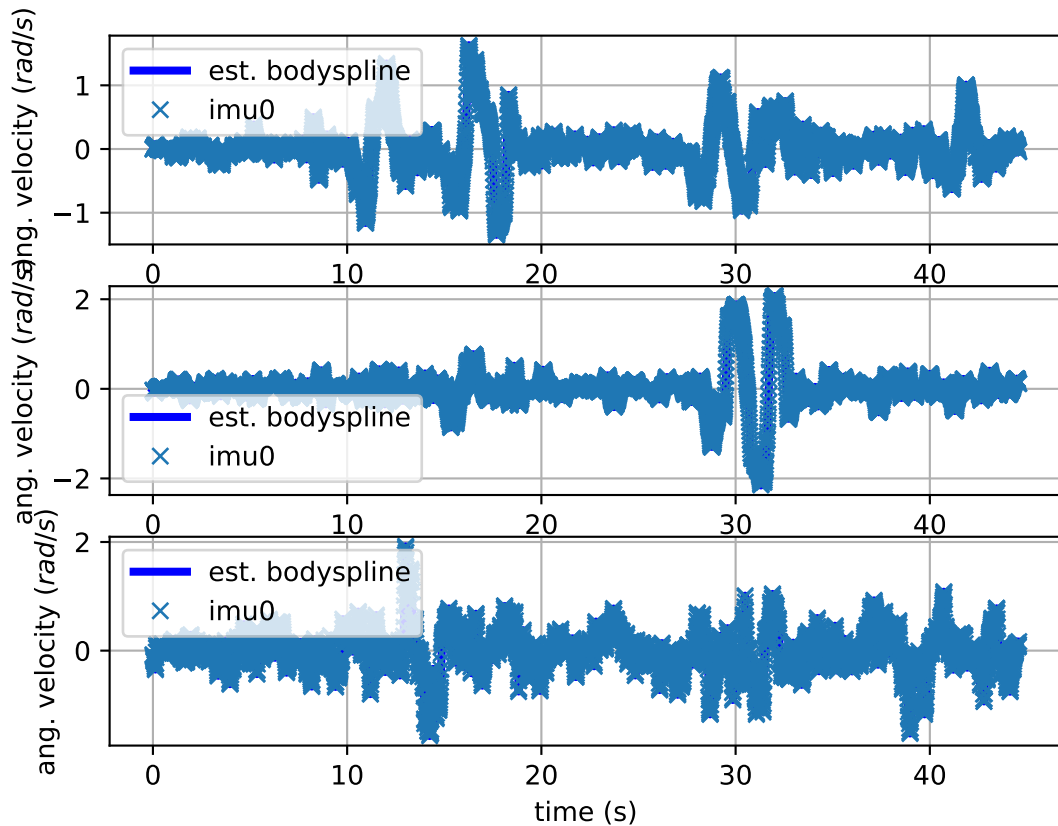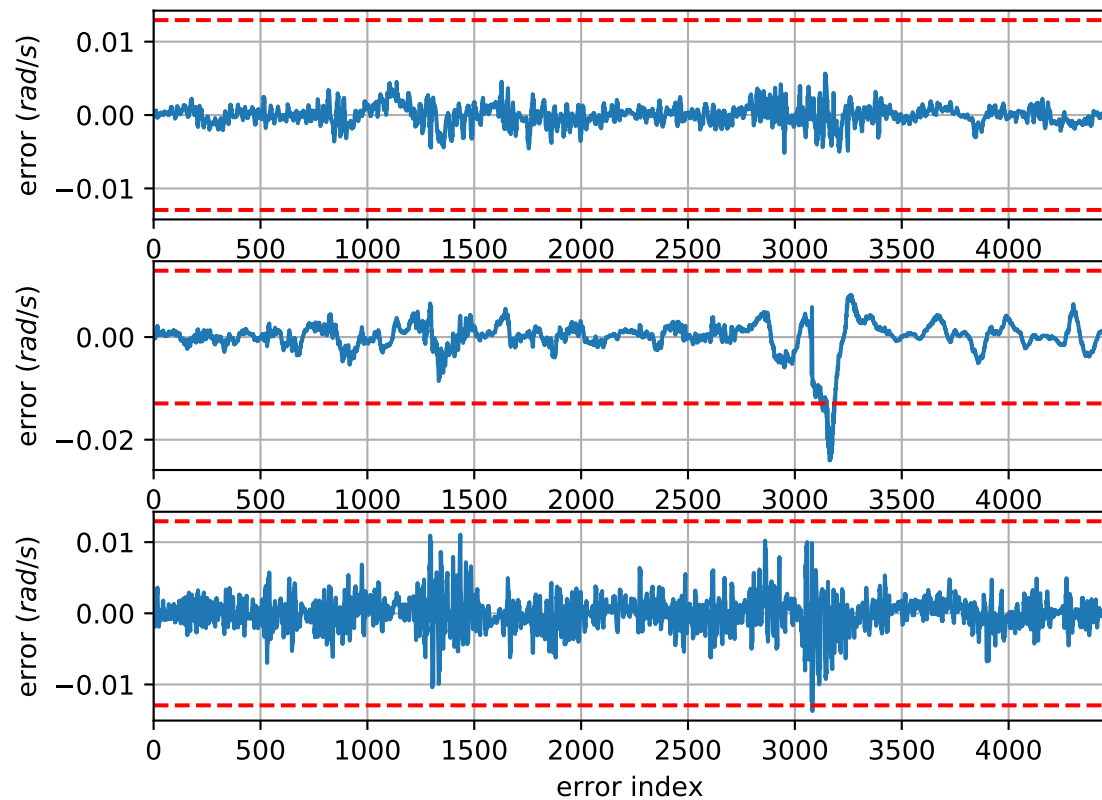
imu0: acceleration error
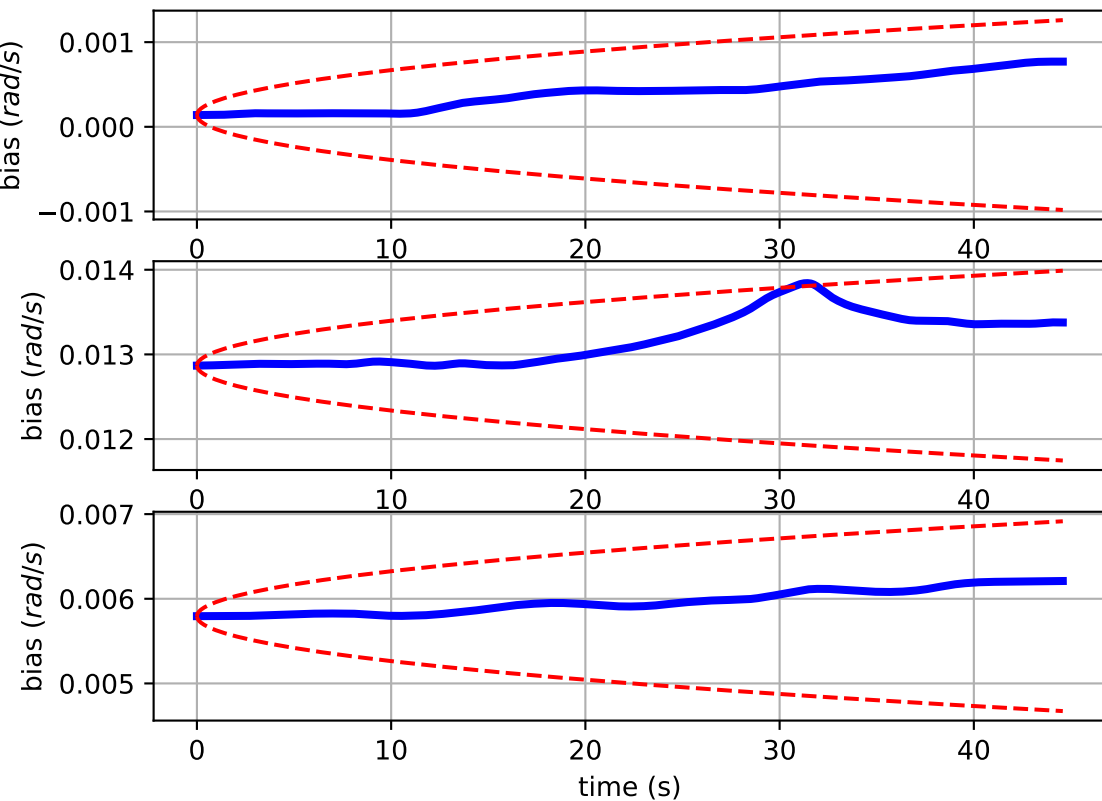
imu0: estimated accelerometer bias (imu frame)

Comparison of predicted and measured angular velocities (body frame)

imu0: angular velocities error

imu0: estimated gyro bias (imu frame)

cam0: reprojection errors