## METR4202 -- Robotics Tutorial 8 – Week 8: Computer Vision Calibration

## **Downloads**

See the METR 4202 Software Page: http://robotics.itee.uq.edu.au/~metr4202/software/index.html

## **Calibration:**

- 1. Install the Calibration toolbox and add the path.
- Download sample images from the class website The format is: rgb: 480x640x3 depth: 480x640

rgbs: 480x640x3x100 depths: 480x640x100

Part 3: To being the toolbox type calib and the gui will display.

Image names	Read images	Extract grid corners	Calibration
Show Extrinsic	Reproject on images	Analyse error	Recomp. corners
Add/Suppress images	Save	Load	Exit
Comp. Extrinsic	Undistort image	Export calib data	Show calib results

\*Ensure that the images you downloaded in part 2 are in your current working directory.

Part 4:

Select Image names from the GUI. You will prompted for Basename camera calibration images (without number nor suffix): Image Image format: tif

## Harris Corners:

Part 1: Install the VLFeat Toolbox

- Part 2: Try the vl\_harris function:
  - idx = vl\_localmax( vl\_harris( vl\_imsmooth( I, 1), 1 ) ); [i,j] = ind2sub( size(I), idx );