CSCM77 Lab Class 2b

Release date: 28/02/2020
Due date: 13/03/2020

This lab is about becoming familiar with stereo-camera calibration, also known as binocular camera calibration.

`CVDL_Server.ipynb` will again be running on our host machine.

`CVDL_Student_Stereo.ipynb` is the notebook you will be running. This notebook utilises images taken from the KinectV2 to attempt camera calibration, calculating the intrinsic and extrinsic parameters of a camera-pair and the patterns used to calibrate it. It also plots both the camera-pair- and pattern-centric views of the world.

☐ Task 2b.1

Run the notebook and understand what is happening. Compare it with your understanding of camera calibration techniques. Capture some of your own calibration examples (≥ 10 images is best), and calibrate based on these images.

1. Download and study the new Jupyter notebook and the demo data.
2. Run `CVDL_Student_Stereo.ipynb`, choosing to either collect new data or load from disk.
3. Calibrate the cameras using the checkerboard patterns observed.
4. Plot both the camera-pair- and pattern-centric views.