(https://accounts.coursera.org/i/zendesk[illegible]ourserahelp?return_to=https://learner.coursera.help/hc/)

Home

(/learn/robotics-perception/home/welcome)

Course Content

(/learn/robotics-perception/home/week/)

Assignments

(/learn/robotics-perception/home/assignments)

Discussions

(/learn/robotics-perception/discussions)

Resources

(/learn/robotics-perception/resources/Wpo75)

Course Info

(/learn/robotics-perception/profiles/54f0bc29d50ebaaad112d663c899916a)

Sorry, the last post was wrong. That's for the results for NAN.....

0 Upvote

Juan Carlos Llorente · 32 minutes ago (/learn/robotics-perception/discussions/9vSpqhblEeaZrBJIefqa4w/replies/VY1VaB

(/learn/robotics-perception/profiles/ca882f103113105e6259b89d2cfbbeb9)

Dear Yatang: I see a few errors in your code. First one: "u w1= uvw1(3);". Shouldn't v1 be uvw1(2)? Same with next

0 Upvote

Juan Carlos Llorente · 26 minutes ago (/learn/robotics-perception/discussions/9vSpqhblEeaZrBJIefqa4w/replies/VY1VaB

(/learn/robotics-perception/profiles/ca882f103113105e6259b89d2cfbbeb9)

Next, check your Jacobian. You set J = [J1; J2; J3]; but the J the handout it should have been J = [J1 J2 J3]', assuming Triangulation as stated in the discussion forums. You ma may not be the issue you are looking for. Moreover, I am the handout: e.g. in (11) the last px should be a py.

0 Upvote

SD

(/learn/robotics-perception/profiles/f34069ce8df6de7dbebfedfb7e760d9f)

Reply

Reply

Help Center