

## GSML Calibration Tutorial

Files required available at [github.com/stef-andonov/nUWAY-CITS3200/tree/master/camera\\_calibration/GSMLCams](https://github.com/stef-andonov/nUWAY-CITS3200/tree/master/camera_calibration/GSMLCams)

Ensure ROS2 environment is sourced:

```
source /opt/ros/humble/setup.bash
```

Create package with:

```
ros2 pkg create gsml --built-type ament_python
```

Copy over pub.py, sub\_separate.py, sub\_separate\_calibrate.py to gsml/gsmll/ directory where the \_\_init\_\_.py file is located.

Replace package.xml and setup.py file contents with that of the ones in the GitHub repository

Go back to the source directory and colcon build, remember to source install/setup.bash

Using the package:

Run publisher node of camera with:

```
ros2 run gsml gsml_publisher
```

Then, run subscriber to take pictures for calibration, use CTRL+C when enough pictures are taken:

```
ros2 run gsml gsml_subscriber
```

Finally, run calibration node to get data in a text file:

```
ros2 run gsml gsml_calibrate
```