# Camera Calibration with ROS and Big Chessboard

Previously, I used code I found in some GitHub repository in order to calibration the camera with a chessboard printed on a A4 paper.

Today, in order to get better more accurate results, I performed the calibration again. But with a big 9x7 chessboard with square size of 10.6cm.

In order to that, I installed the ROS Camera Calibration that can be found in the following repo:

https://github.com/ros-perception/image_pipeline

And the documentation for this calibration is in the following link:

http://wiki.ros.org/camera_calibration

Afterwards, in order to calibration the camera I performed the following steps:

- In the first terminal I ran the following command:
  Roscore
- In the second terminal I ran the following command:
  Roslaunch ueye_cam dso.launch (documentation for this is in the github repo)
- In the last terminal I ran the following command:
  Rosrun camera_calibration cameracalibrator.py –size 8x6 –square 0.086 image:=/camera/image_raw camera:=/camera

After I ran that final command, I pointed the camera on the chessboard, and the calibration started. I pointed the camera at the chessboard from different angles, until the "Calibrate" button in the GUI turned orange and finally, I pressed on it and it finished the calibration and printed the results!