

# Journal de bord MOOREV- Stéréovision\_Calibration

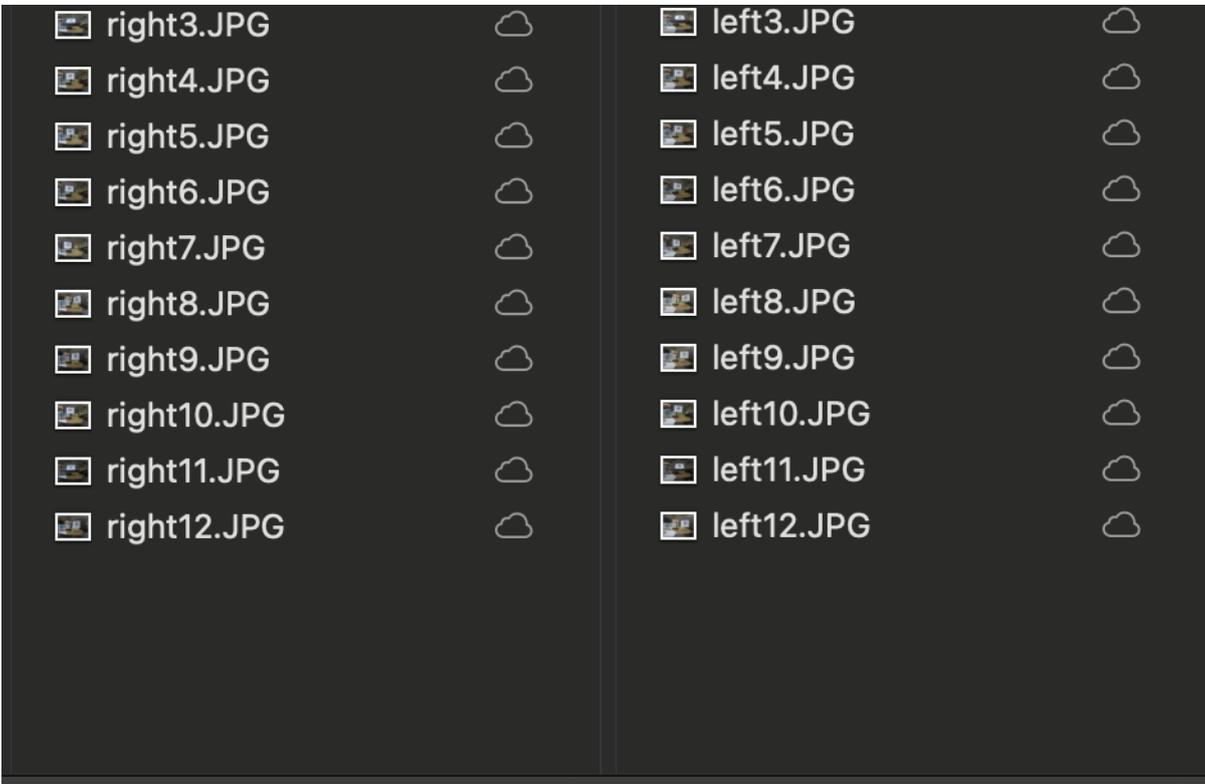
## Journal de bord:

Vendredi 7 avril:

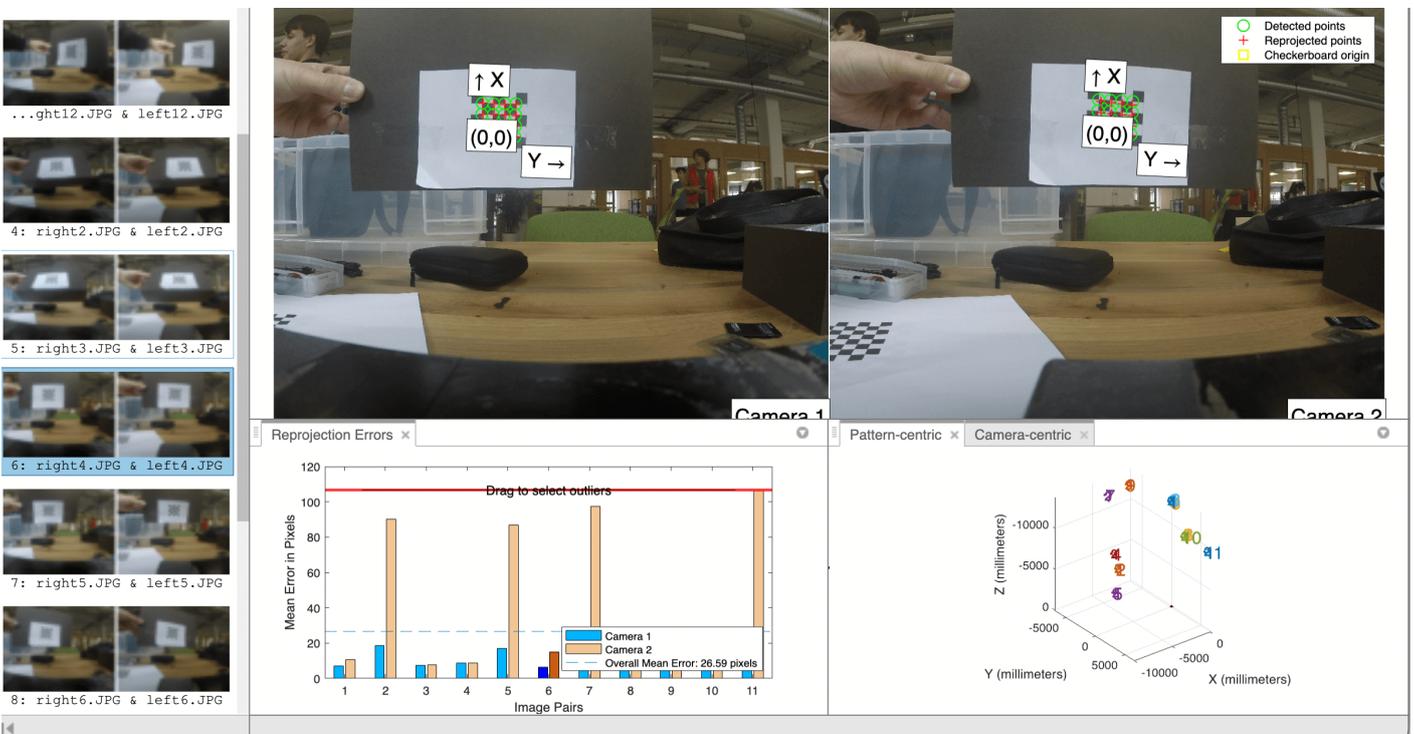
- On a imprimé préalablement des échiquier pour la calibration.
- On a utilisé les 2 Gopros Heroes 3+ pour prendre des photos.
- On a placé les caméras et l'échiquier à une distance de 20cm



- On a pris des photos de l'échiquier dans plusieurs angles.
- On les a triés et séparés par photo droite et gauche,



-On a calibré les photos grâce a l'application "Stereo Camera Calibrator" de MatLab

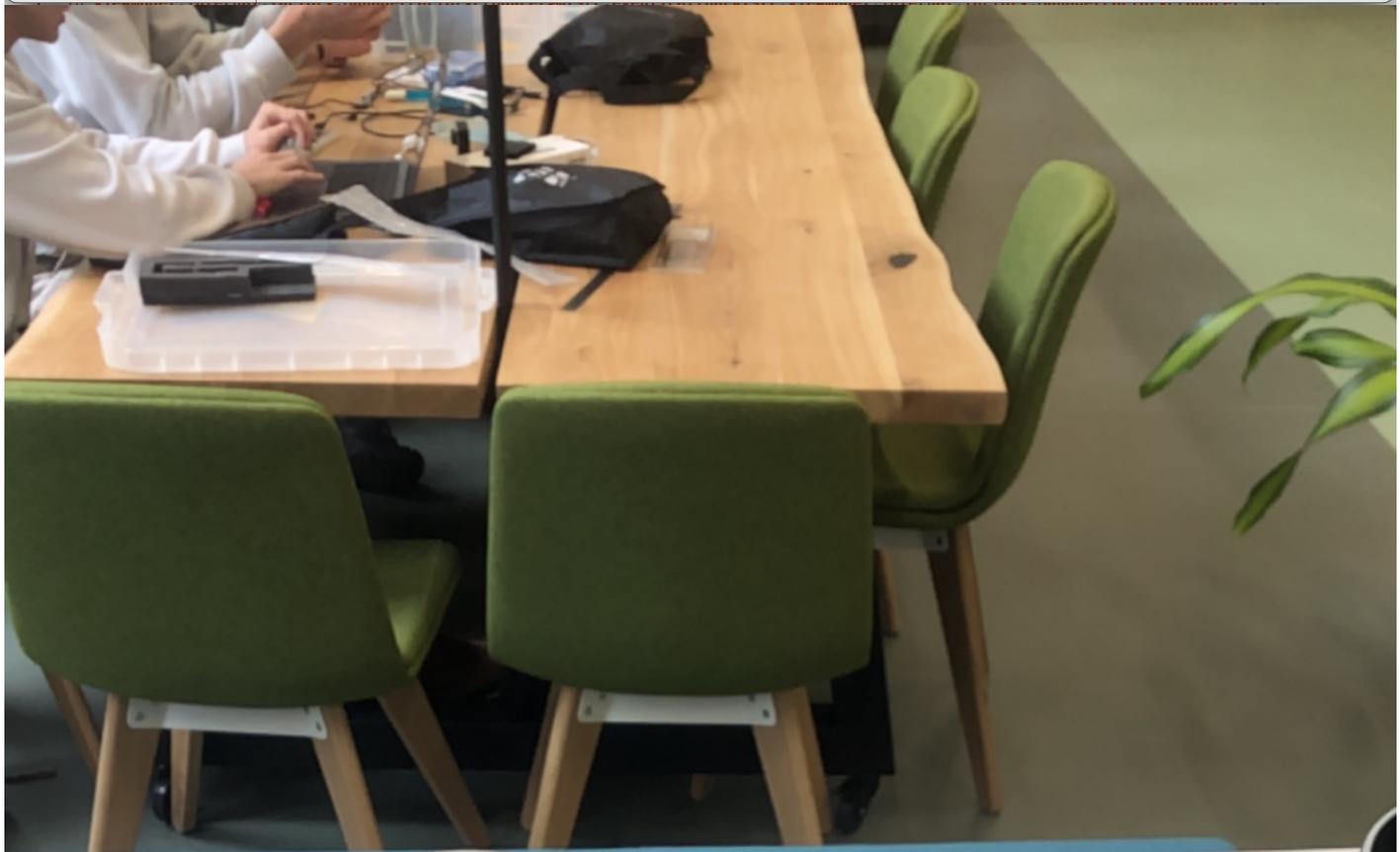


Mardi 11 avril:

-On refait de la calibration, on réduit la marge d'erreur de la reprojection pour être environ en dessous de 10 pixel

The screenshot displays the Stereo Camera Calibrator software interface. The top menu bar includes options like 'New Session', 'Open Session', 'Save Session', and 'Add Images'. The main workspace shows two camera views of a checkerboard target, with detected points and reprojected points overlaid. A legend indicates: green circles for detected points, red crosses for reprojected points, and yellow squares for checkerboard origin. Below the images, a 'Reprojection Errors' bar chart shows the mean error in pixels for five image pairs, with Camera 1 in blue and Camera 2 in orange. A horizontal red line indicates a threshold at 3.5 pixels, and a dashed blue line shows the overall mean error at 1.87 pixels. A 3D plot on the right shows the point cloud in a coordinate system with X, Y, and Z axes in millimeters.

Image Pairs	Camera 1 (Mean Error in Pixels)	Camera 2 (Mean Error in Pixels)
1: D1.JPG & G1.JPG	~1.5	~1.5
2: D2.JPG & G2.JPG	~1.4	~2.1
3: D3.JPG & G3.JPG	~2.1	~3.8
4: D4.JPG & G4.JPG	~1.8	~1.1
5: D5.JPG & G5.JPG	~2.0	~1.5



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Revision #3

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