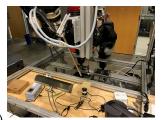# DVRK stereo camera calibration and model registration

- **Project Goal**: Phantom placed in the camera view needs to be registered with the PSM robot.
    - First perform a hand-eye calibration to know the relationship between the camera and the robot.
    - Detect the phantom model in the camera view and register the model to the camera.
    - Final get the registration between the robot and the model.
- **Size group:** 1-2
- **Skills:**
    - C++, Matlab/Python.
    - Knowledge of ROS would be very helpful.
    - Image processing, Registration, Hand-Eye calibration
- **Mentors:**
    - Preetham Chalasani (pchalas1@jhu.edu)
    - Anton Deguet (anton.deguet@jhu.edu)