

Overview

The computer vision subsystem of the rover is utilized in the Navigation, Surface Sampling and Maintenance Tasks of ERC. It is accomplished through the use of the rover cameras: Gripper camera (digital Arducam), Bottom chassis camera (digital Arducam), Front chassis camera (Depth). The subsystem can be further divided in two sections, ArUco Detection and Object detection, both aiding in different parts of the ERC competition.

On the RoboWiki, please read the page "ArUco" for understanding ArUco Detection, and "YOLO" for understanding general object detection through the YOLO framework (such as detecting a button on the maintenance board).

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