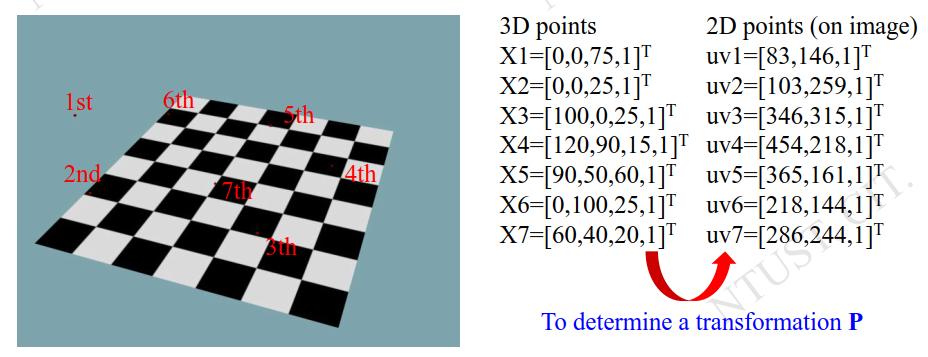
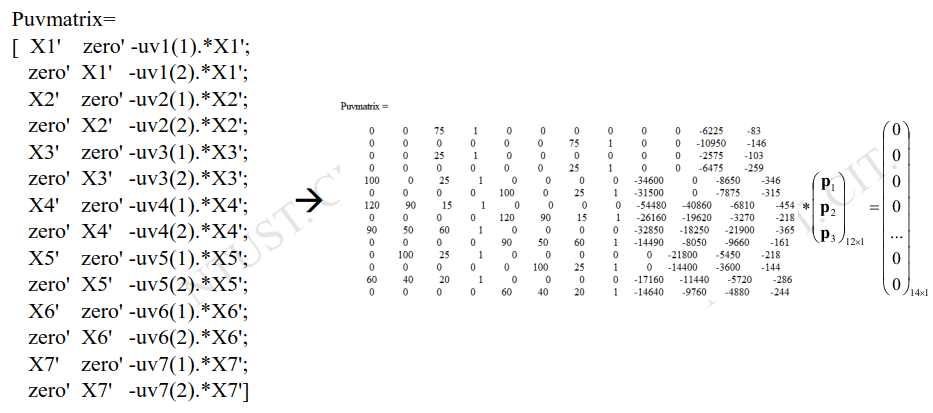
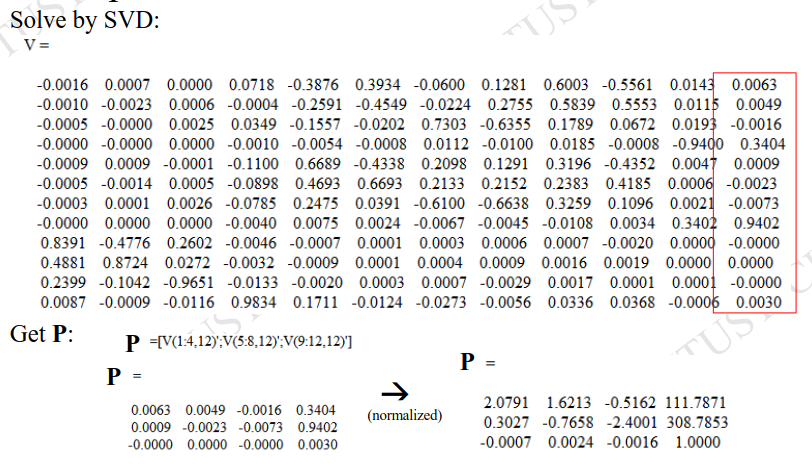
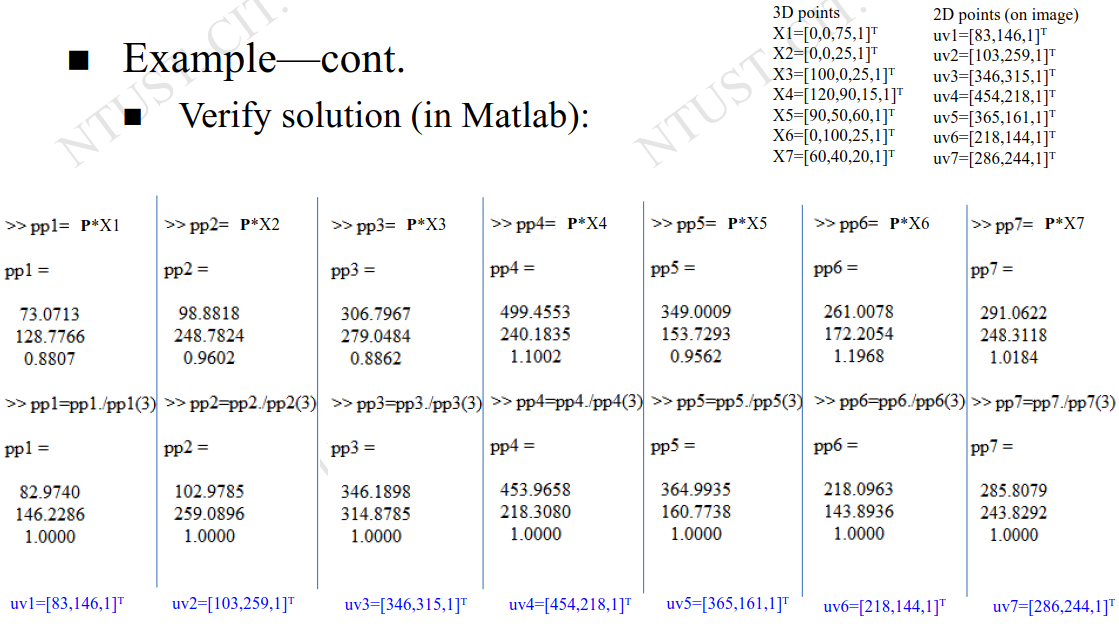
計算P矩陣



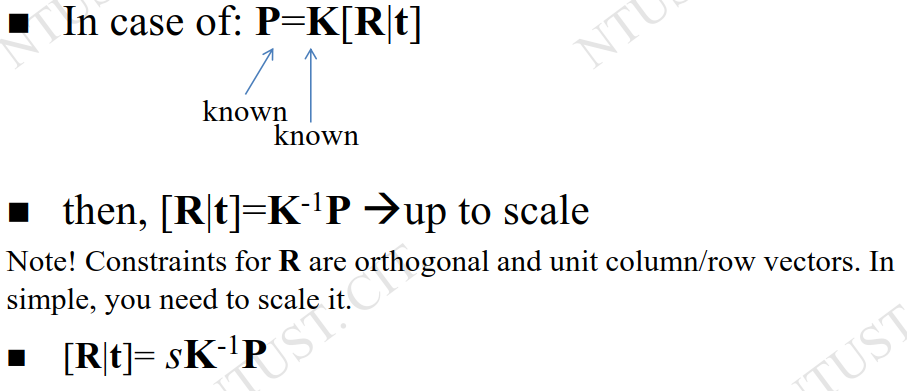




檢查P矩陣的精確度

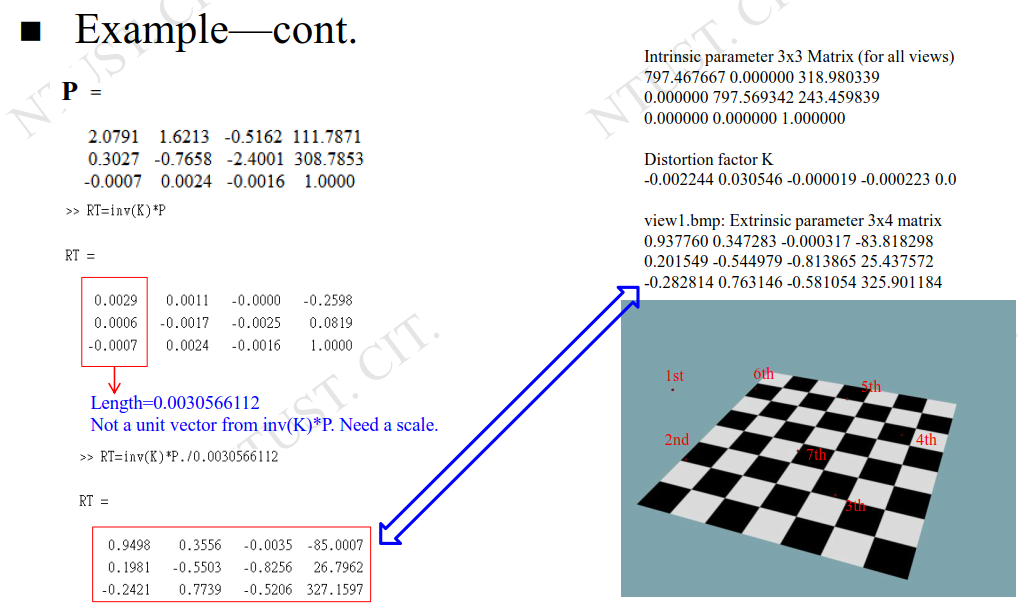


分解P矩陣



已知內部參數K矩陣，可得知[R|T]，需要正規化，即可得相機之相對位置

作業則是透過IAC/Chang的方式去得到K



How to use SVD to solve over-estimated homogeneous matrix



