Group 45

Lab 4

**EX 4.6**

The residual vector between the re-projected points and known points.

We have 3 unknown variables in U=

The camera equation is Pi == ………(1)

We can see that each camera has 3 equation and one extra unknown, so we need 2 view for every on. Hines, we rewrite (1)

Pi=

Ui =

**EX 4.8**

Formulas for the partial derivatives in the Jacobian of .

Suppose

(x, y, z) to (u, v, w)

In our case we have