

Algorithmic choices

- 1) Generate SIFT features and descriptors for each image
- 2) For each image i and $i+1$, estimate rotation by match the images and estimate E robustly using parallel RANSAC as described in the project
- 3) Calculate absolute rotation by chaining them.
- 4) Do step 2 by only for the init image pair and get the 3D points for the pair.
- 5) For each image, match with 3D points from init pair and each image and estimate T robustly (similar to RANSAC to identify best T and estimate T is similar to `estimate_camera_DLT` but considering R is already known)
- 6) With R and T now for each camera, triangulate 3D points between i and $i+1$ images. Also removing the far away and points.