Algorithmic choices

1) Generate SIFT features and descriptors for each image

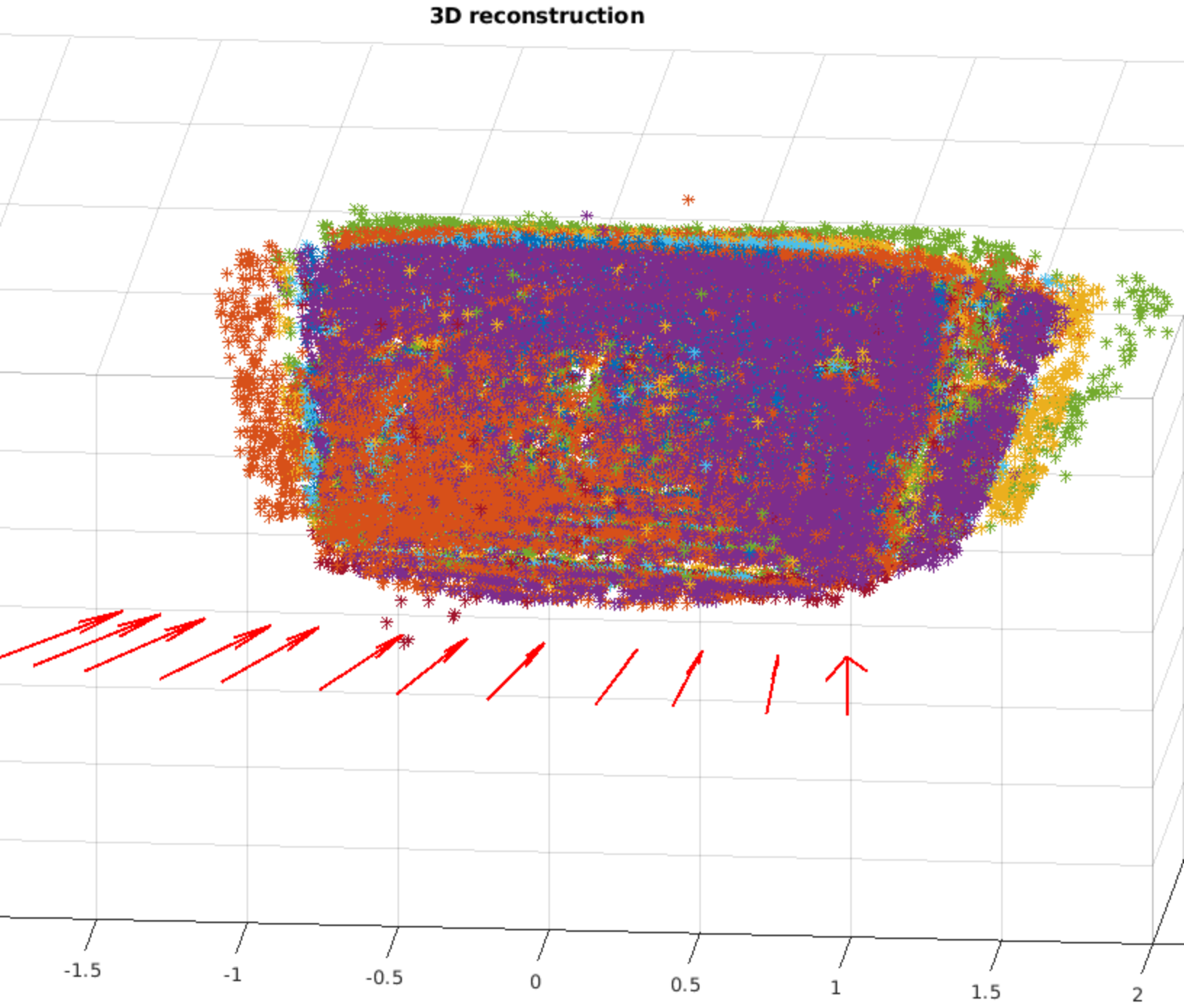
2) For each image i and i+1, estimate rotation by match the images and estimate E robustly using parallel RANSAC as described in the project

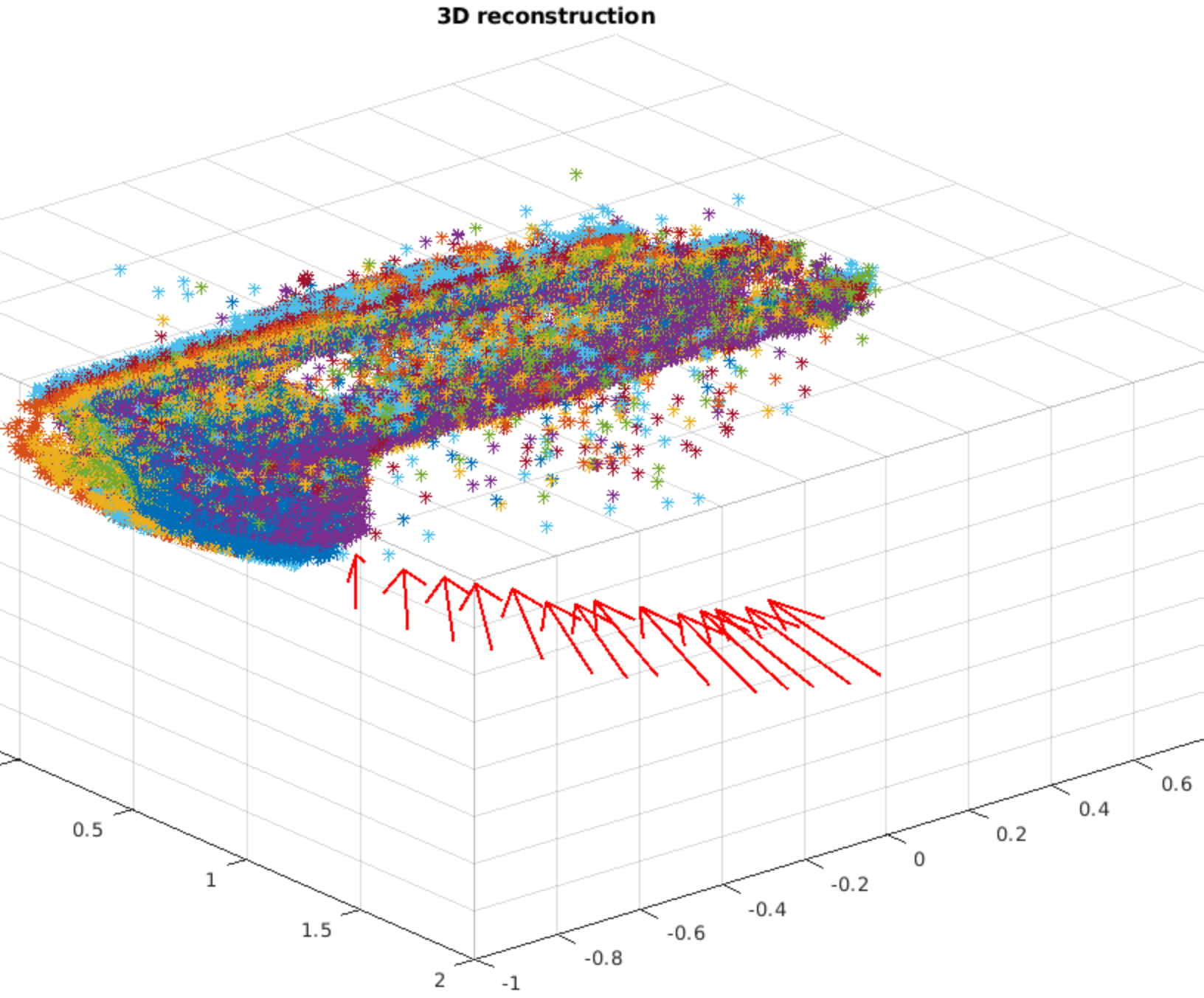
3) Calculate absolute rotation by chaining them.

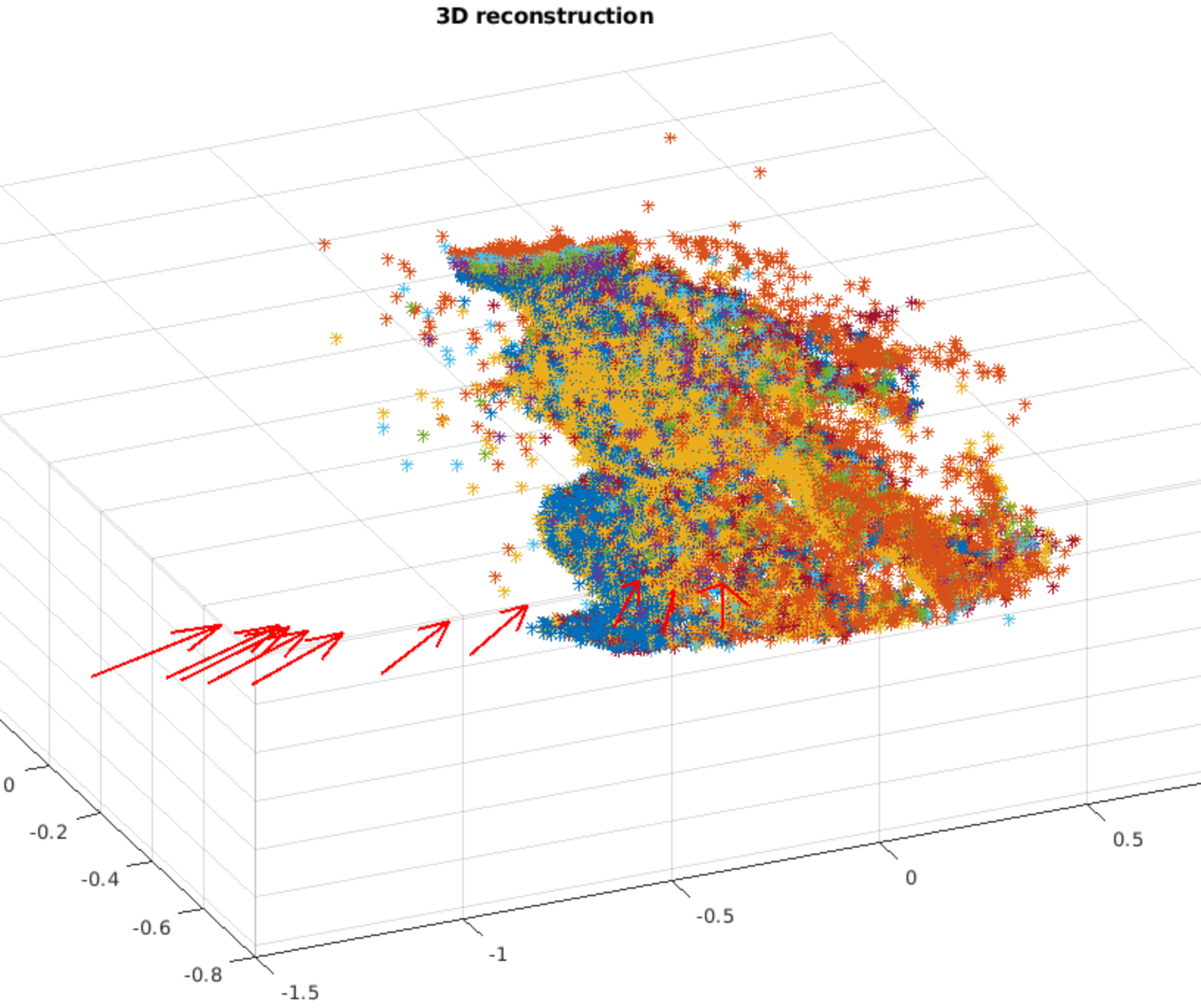
4) Do step 2 by only for the init image pair and get the 3D points for the pair.

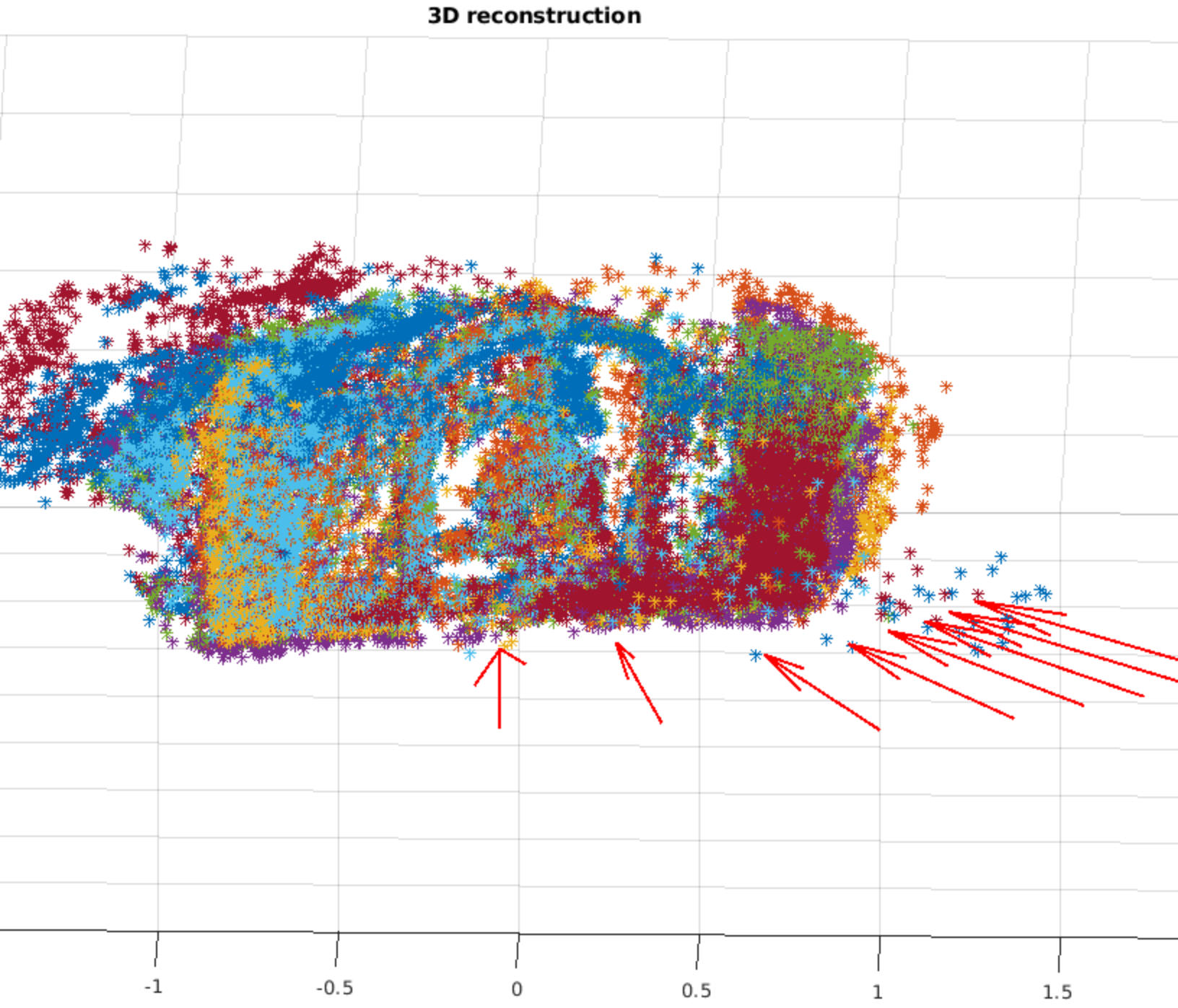
5) For each image, match with 3D points from init pair and each image and estimate T robustly (similar to RANSAC to identify best T and estimate T is similar to estimate_camera_DLT but considering R is already known)

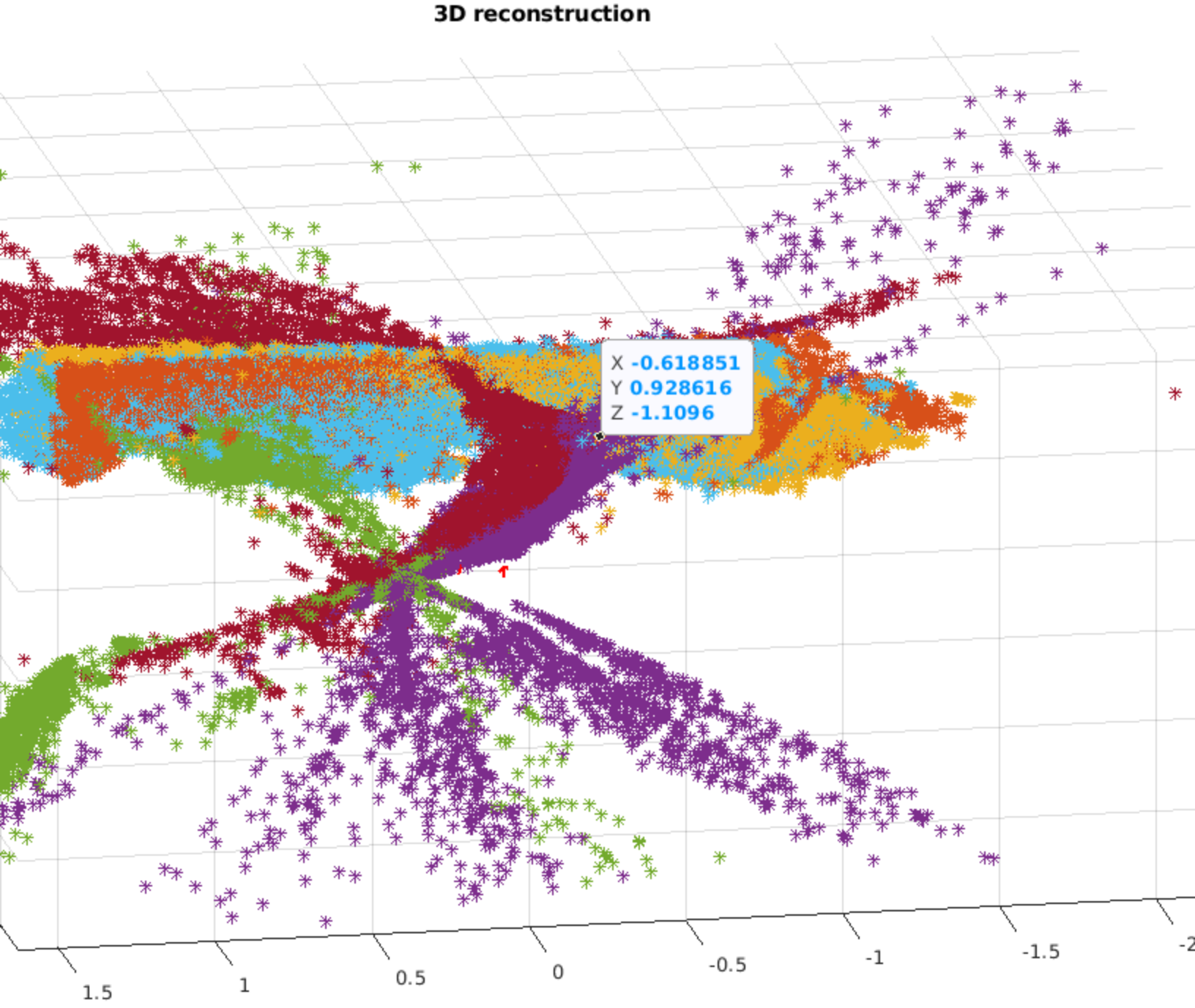
6) With R and T now for each camera, triangulate 3D points between i and i+1 images. Also removing the far away and points.


3D reconstruction
-1.5
-1
-0.5
0
0.5
1
1.5
2


3D reconstruction
0.5
1
1.5
2
-1
-0.8
-0.6
-0.4
-0.2
0
0.2
0.4
0.6


3D reconstruction
0
-0.2
-0.4
-0.6
-0.8
-1.5
-1
-0.5
0
0.5


3D reconstruction
-1
-0.5
0
0.5
1
1.5


3D reconstruction
X -0.618851
Y 0.928616
Z -1.1096
1.5
1
0.5
0
-0.5
-1
-1.5