Inferring 3D Structure

- In order to properly find the intrinsic parameters of the camera, we need to infer some 3D structure from the environment. To that end, we need to do the following:
  - Find keypoints via *Feature Detection*.
  - Match these keypoints through *Feature Matching*.
  - Summarize the matches into *Tracks*.
  - Find camera parameters and 3D points through *Optimization*.
- Each of these steps will be described in more details.