Bundle Adjustment

Using the image tracks, the final step of the problem is creating and solving a non-linear system of equations on the form:

$$\mathbf{x}_j = f(\mathbf{X}_i)$$

Where $\mathbf{X}_i$ represents a 3D point in the scene and $\mathbf{x}_j$ is the projected image point of $\mathbf{X_i}$ from camera j. Here, $f(\cdot)$ represents function that transforms the 3D point to the image point.