Algorithm: *Associating 2D points.*

∀ camera i and $j \neq i$

  ∀ x_{in} point in camera i

    Find epipolar line l_{in} in camera j

    ∀ x_{jm} point in camera j

      $b_{nm} = \text{distance}(x_{jm}, l_{in})$

    $D_{ij} = \{b_{nm}\}$, possible associations

Algorithm: *Best match.*

∀ camera i and $j \neq i$

  $\tilde{D}_{ij} = \text{valid}(D_{ij})$

  $b^{ij}_{nm} = \text{minimum}(\tilde{D}_{ij})$

  $x_{in}x_{jm}$ pair corresponding to b^{ij}_{nm}

  $d_{ij} = \text{distance}[\text{rays\_projetion}(x_{in}, x_{jn})]$

$d = \text{minimum}(\{d_{ij}\})$