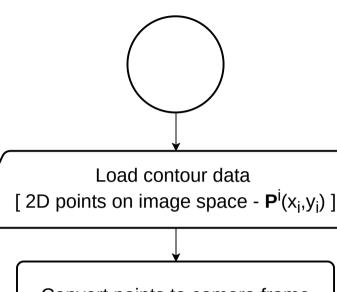
## Position



Convert points to camera frame  $\mathbf{P}^{i}(x_{i},y_{i}) \rightarrow \mathbf{P}^{c}(x_{c},y_{c},z_{c})$ 

