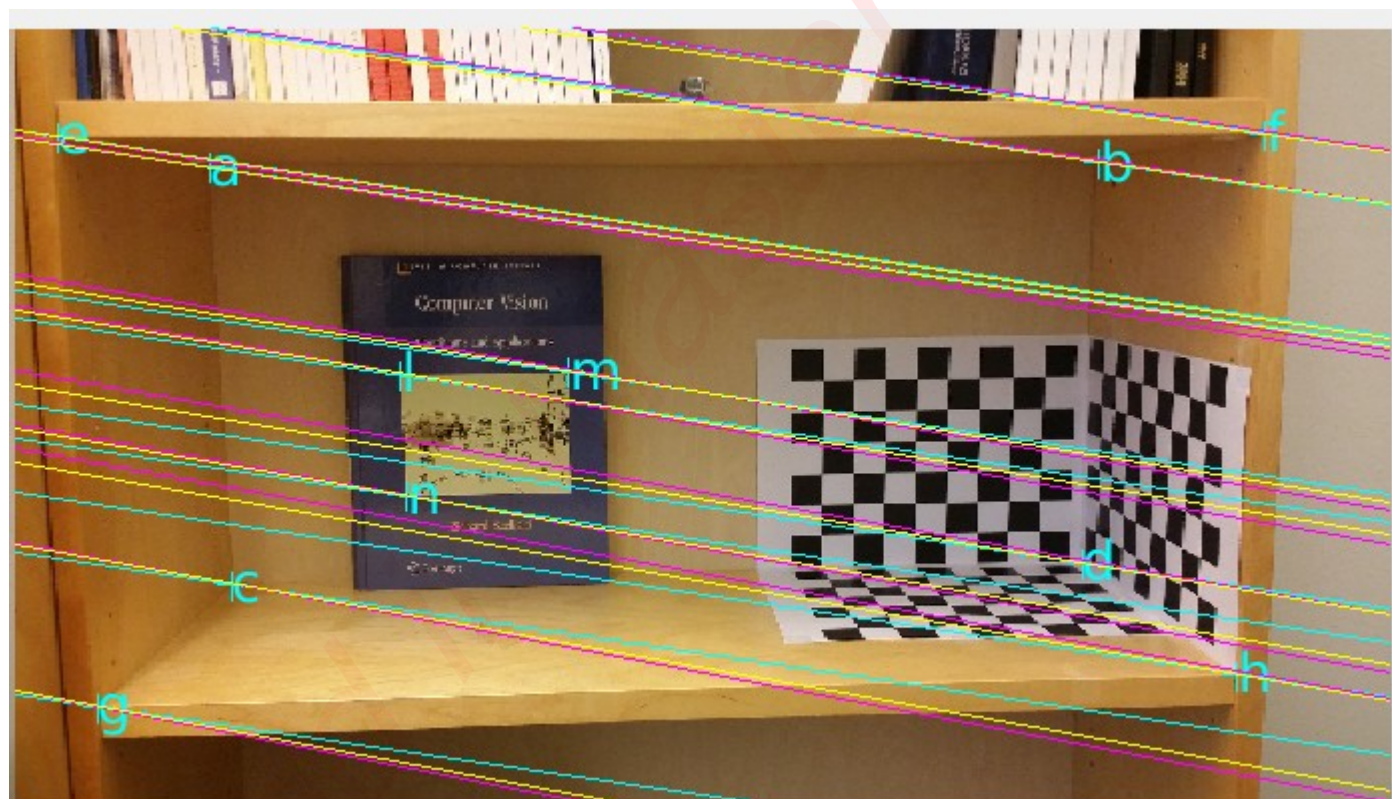
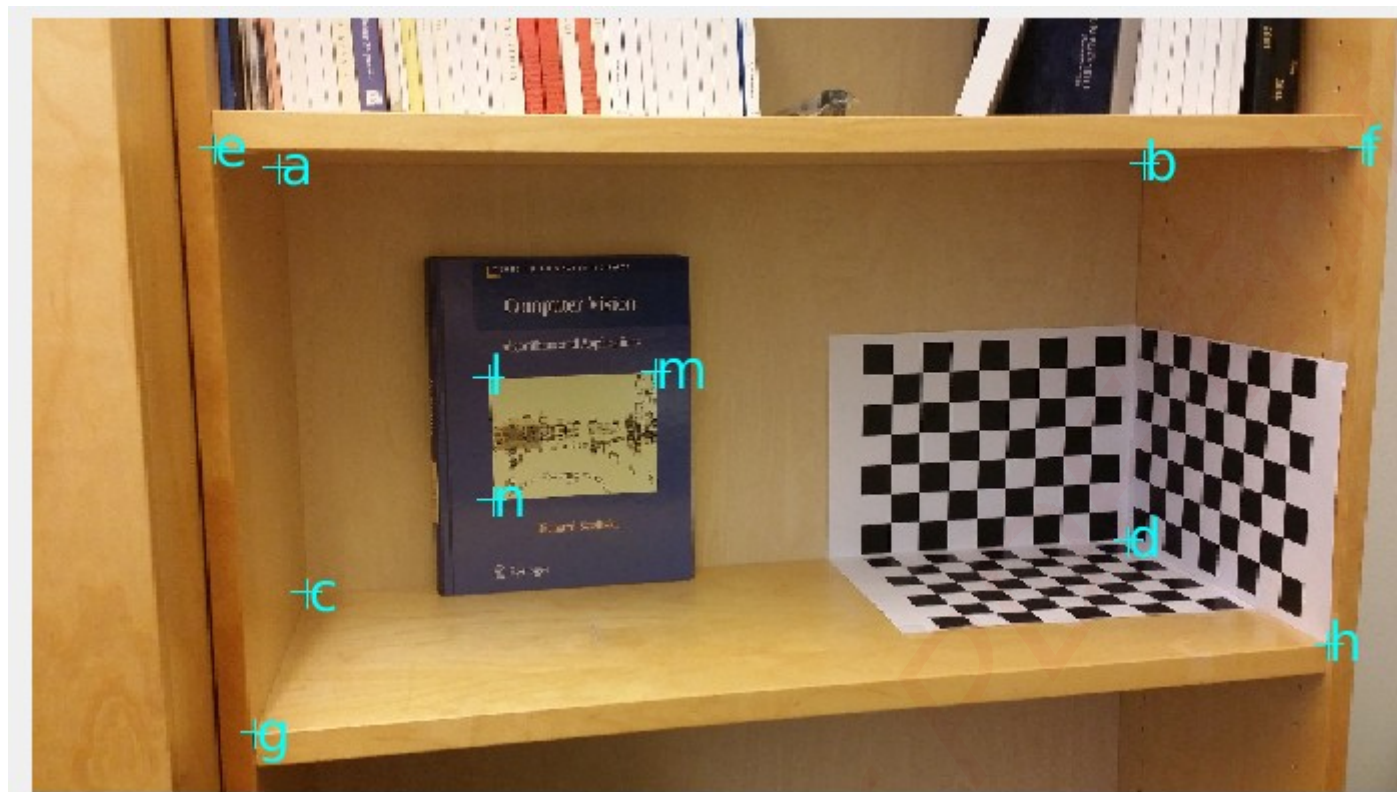


Task 1



Task 2

- a) Cameras are calibrated here using DLT (Direct linear transform) algorithm, as delineated in lection 11, slide 22
- b) By using projective structure from motion with no constraints structure can be recovered up to 4x4 projective transformation, which can preserve intersection and tangency.
More information is needed to get the structure shown more consistently.
- c) lens distortions, focal lengths, mutual position of the cameras... more parameters of cameras



cted cuboid

