- Normalize image points

  - **Centroid is at the origin**. We create the matrix T_{trans} for each camera like this:
  $$\begin{bmatrix} 1 & 0 & -\mu_x \\ 0 & 1 & -\mu_y \\ 0 & 0 & 1 \end{bmatrix} \tag{1}$$
  And we multiply each point of the cameras to they corresponding T matrix like this: Tx_i.

  - **RMS distance from the origin is $\sqrt{2}$.** First compute the RMS of the available points:
  $$\sqrt{\frac{1}{n} \sum_{i=1}^{n} \left((x_i - \mu_x)^2 + (y_i - \mu_y)^2 \right)} \tag{2}$$
  Then create T_{scale} and multiply it to each point in the camera. T is:
  $$T_s = \begin{bmatrix} \sqrt{2}/RMS & 0 & 0 \\ 0 & \sqrt{2}/RMS & 0 \\ 0 & 0 & 1 \end{bmatrix} \tag{3}$$

- **Multiply each point by $T_n = T_s T_t$ like this $[uv1]' = T_n x$. Do it for each camera.**

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