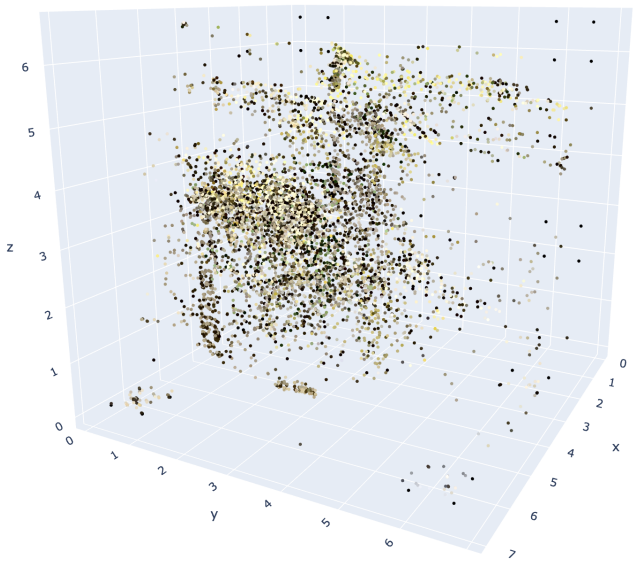
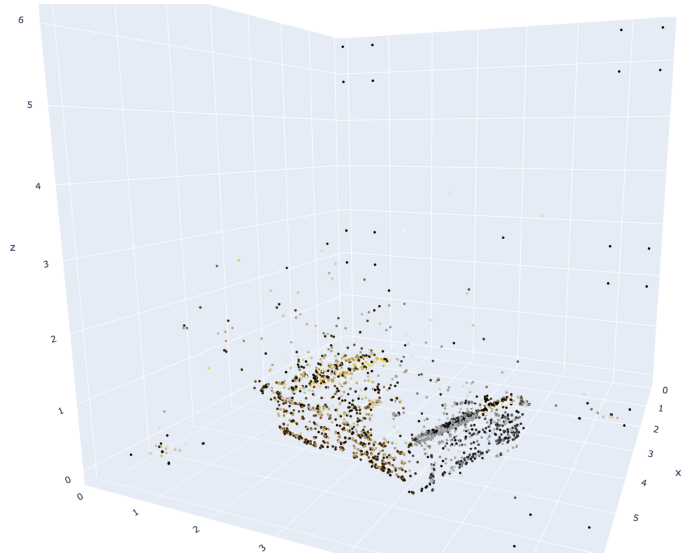
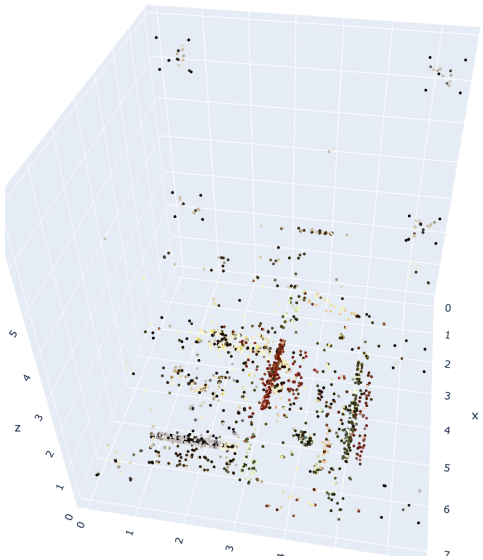
1. My RANSAC removes the possibility of accidentally choosing an outlier matrix to be labeled as the true fundamental matrix, therefore the resulting 3d reconstructed image to be reasonably similar to the ground-truth. I also observed that increasing the number of iterations would increase the confidence of the best matrix as we had more samples to choose from and increased the accuracy of the 3d plotting.

2. Below are three results of my implementation.


z
y
x


z
x


z
x

Incorrect matches would make a wrong guess of the 3d-coordinate from the 2d coordinates as we use a pair of 2d points to estimate the 3d-coordinate in matches_to_3d function. It also affects our ransac algorithms especially when the number of iterations is relatively small because they would not be detected as outliers and the estimated fundamental matrix could lose accuracy because of the incorrect matches. That said, when num_iters in ransac is not large enough, I observed that the reconstructed 3d coordinates tend to be inaccurate.