CAM0 = FRONTAL CAMERA

CAM1 = LATERAL LEFT CAMERA

CAM2 = LATERAL RIGHT CAMERA

H0,H1,H2 = ROTOTRASLATION MATRIX OF EACH CAMERA

You can Use ARUCO 444 seen by the frontal camera to refer all to it

TO USE THE .png IMAGE YOU HAVE TO EQUALIZE THEM (see how to do in Main.m)