Landmarks: Numpy matrix with row\_number = id – N X 3 matrix

Id:

Real\_world x,y,z

Frame:

Seq\_no. =

Id = filename

Pose\_estimate

2D keypoints List:

2D keypoints des list:

Current > previous > Landmar

ks

Input (prev and landmarks)

Small Grid

Camera matrix: [[3502.552 0. 2032.44 ]

[ 0. 3507.666 1466.435]

[ 0. 0. 1. ]]

Dist: [[-0.285 0.153 0. 0. -0.066]]

ret: 0.7317761704076537

array([[-2.85076025e-01, 1.52582102e-01, 1.88230160e-04,

2.70029391e-04, -6.63716833e-02]])

mtx

Out[28]:

array([[3.50255214e+03, 0.00000000e+00, 2.03244043e+03],

[0.00000000e+00, 3.50766569e+03, 1.46643503e+03],

[0.00000000e+00, 0.00000000e+00, 1.00000000e+00]])

Big Grid:

array([[3.52778842e+03, 0.00000000e+00, 2.02004973e+03],

[0.00000000e+00, 3.50216054e+03, 1.47187186e+03],

[0.00000000e+00, 0.00000000e+00, 1.00000000e+00]])

array([[-0.28367083, 0.15514031, -0.0003013 , -0.00040798, -0.06842292]])