

④

$$N_{tt} \Delta t = \bar{h}_t$$

Easy to invert. \rightarrow choice.

Obtain 3D points Given Δt .

$$\Delta u = N_{ku}^{-1} (h_u - N_{kt} \Delta t)$$

Data without control points

Constraints — center of mass of 3D points should not change. 7 degrees of freedom.

orientation should not change.

— New constraints can be expressed with constraint matrix H with $H \hat{x} = 0$

A Remains on outliers.

instead of using Gaussian model (noise) use a robustified robust version of bundle.