

# Epipolar Geometry

Given a set of input images, compute the fundamental matrices for each pair. Compute the epipoles of a fundamental matrix and display them in respective pairs of images. Display also epipolar lines of the feature points used in the computation. Estimate camera calibration matrices from the fundamental matrix and determine the 3-D coordinates of the feature points identified by the corners and intersecting points of straight lines. The set of input images are attached with this assignment.

Please implement your programs in MATLAB or C++/OpenCV, with necessary user's interfaces for identifying the corresponding points, and visualization of your results and input. Please provide documentation for compiling and running the program in a README file. The whole project should be submitted in a single tar or zip file.

## SUBMISSION STATUS

This assignment will accept submissions from **Saturday, 5 March 2016, 12:00 AM**