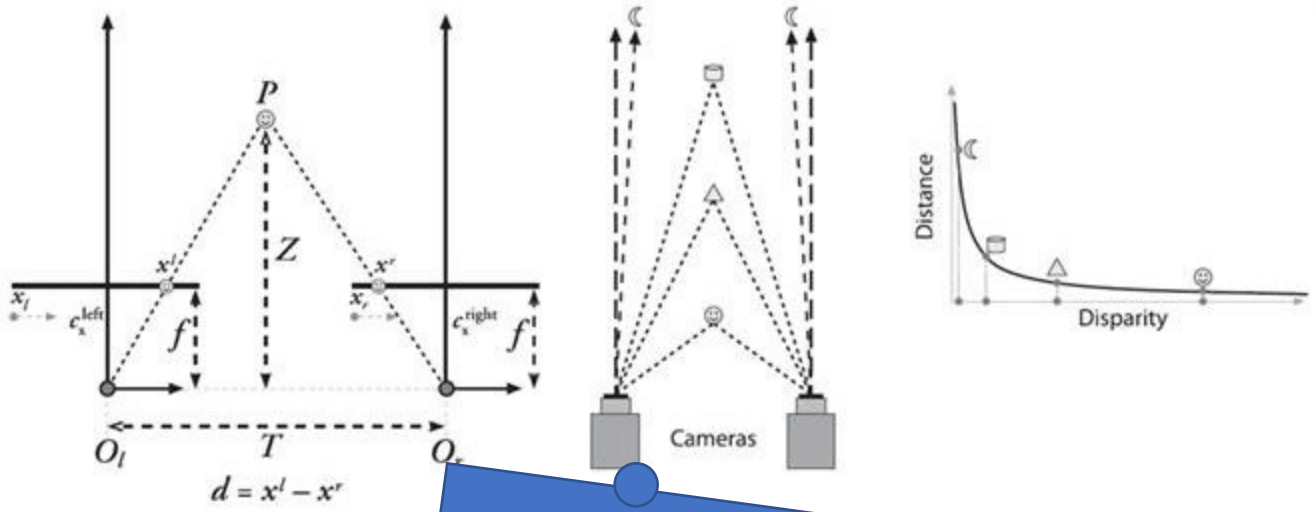
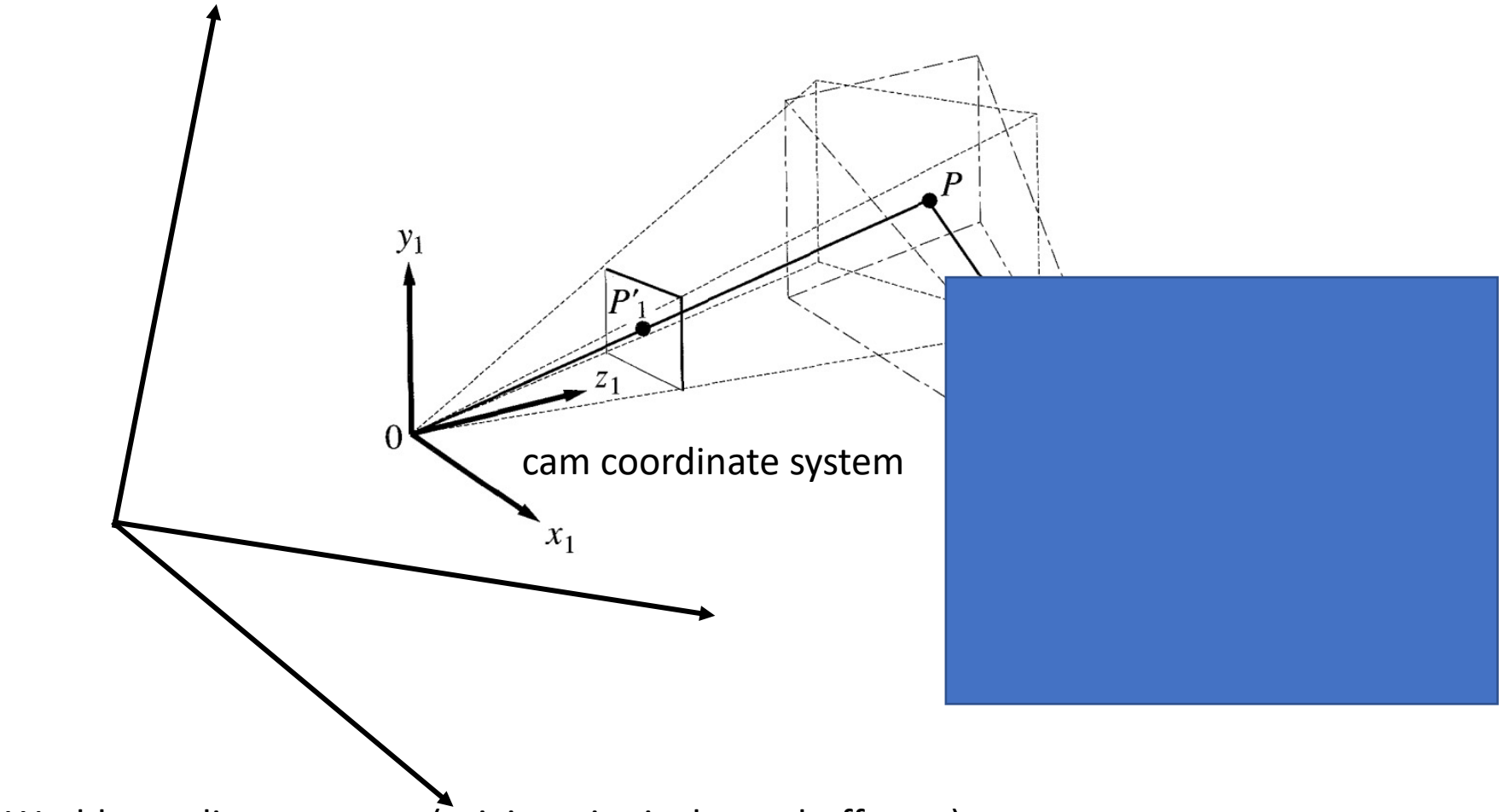
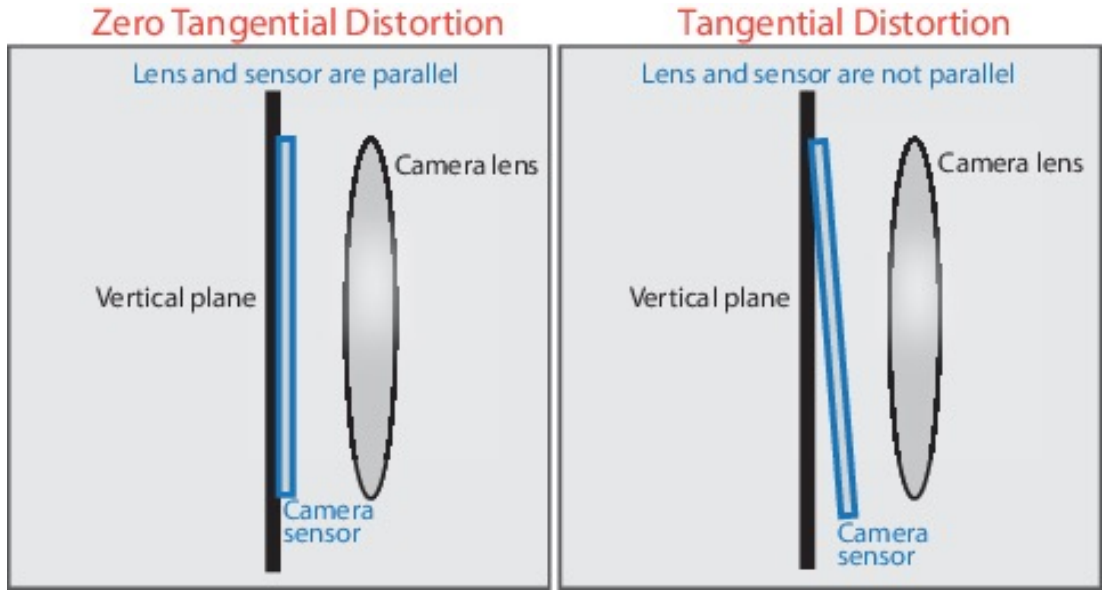
Overview of dual camera projection: (depth)

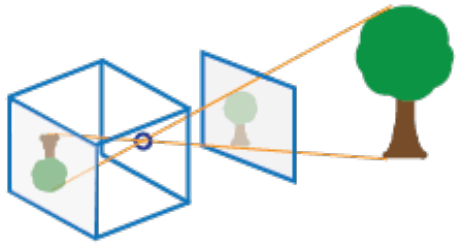


For single camera projection: (extrinsics: R+T)

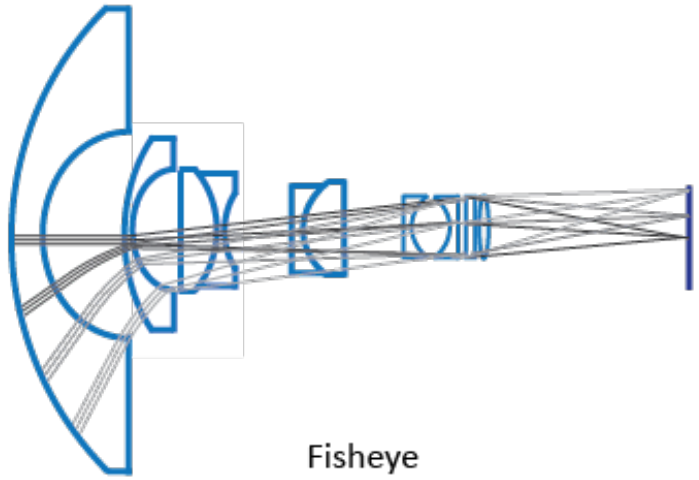


For single camera projection: (intrinsics)





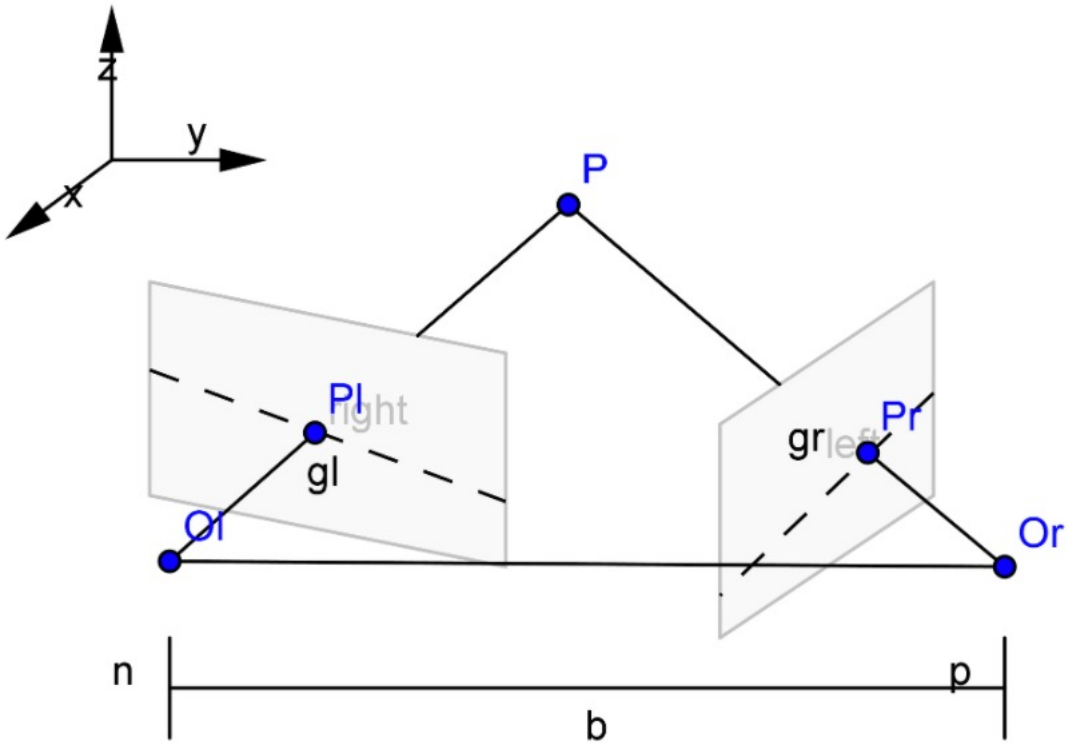
Pinhole



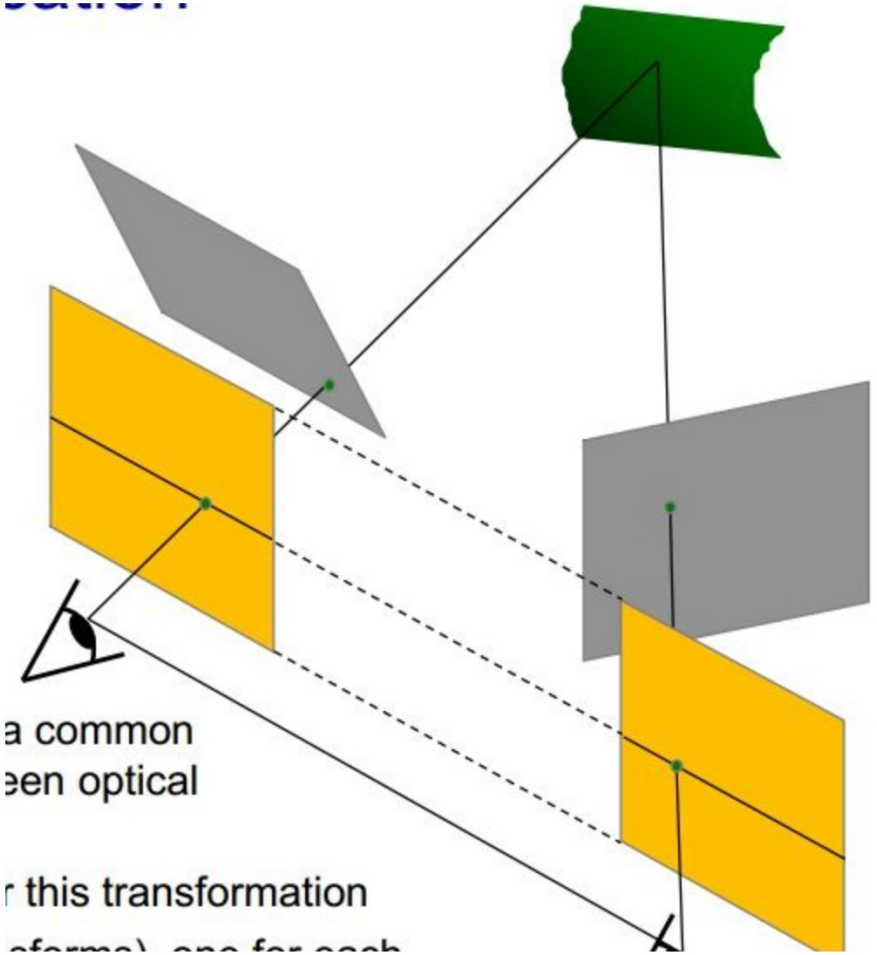
Fisheye

[camera calibration]

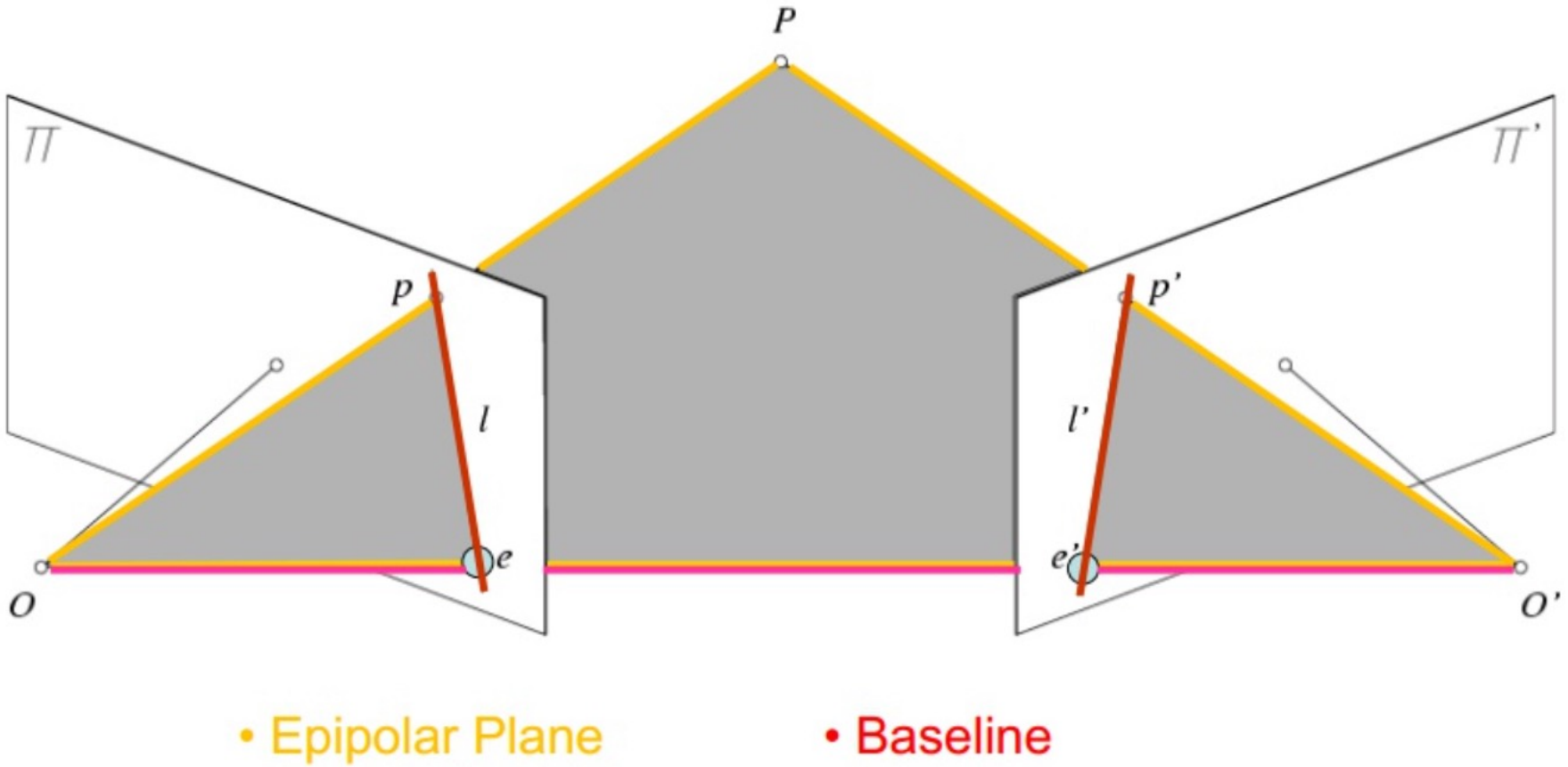
For dual camera projection: (biased)



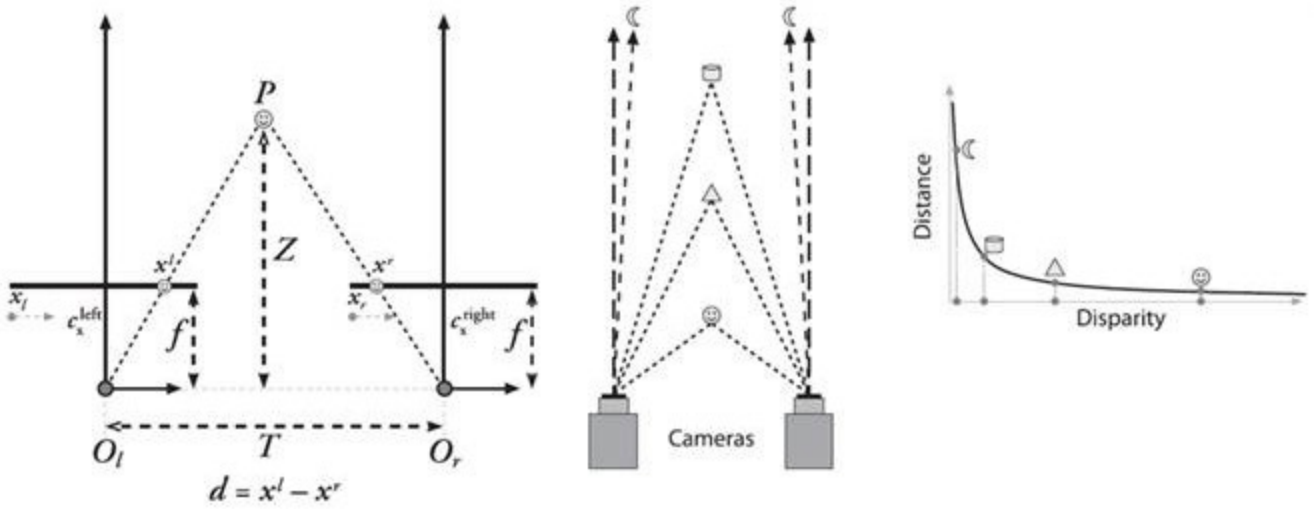
For dual camera projection: (calibration)



For dual camera projection: (calibration)



For dual camera projection: (depth)



$$\frac{T-(x^l-x^r)}{Z-f}=\frac{T}{Z} \quad \Rightarrow \quad Z=\frac{fT}{x^l-x^r}$$

For dual camera projection: (feature matching)