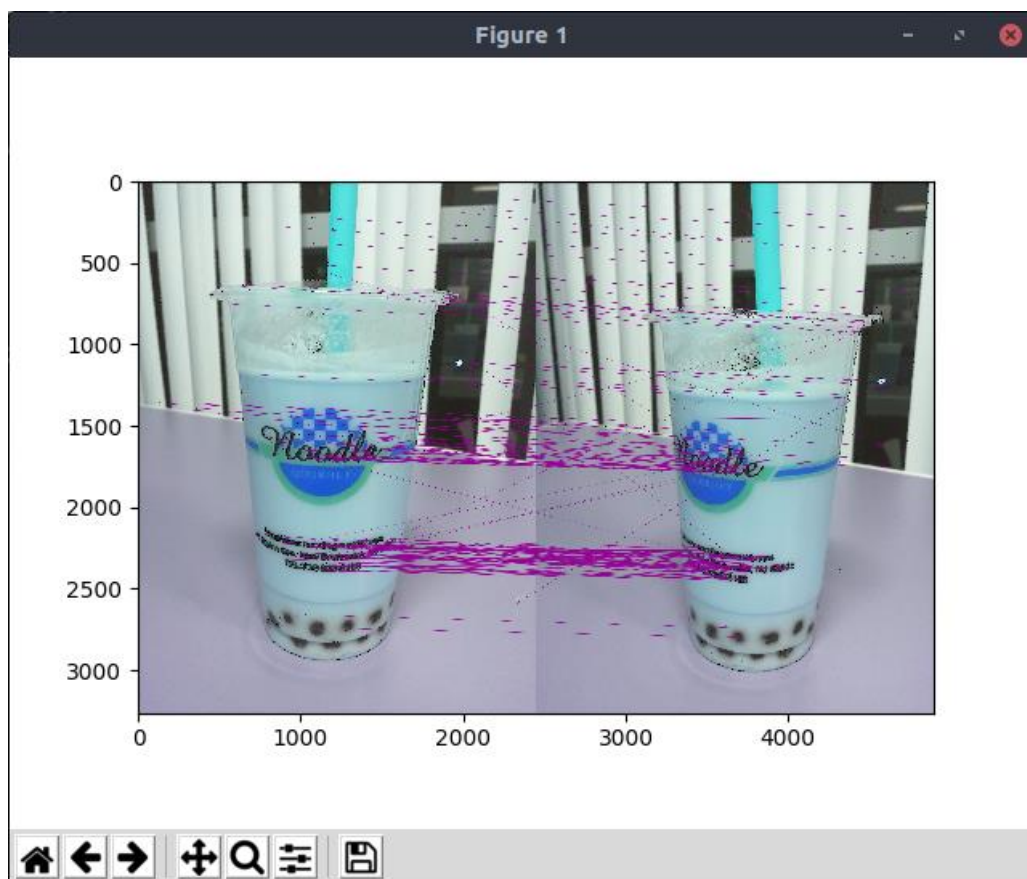




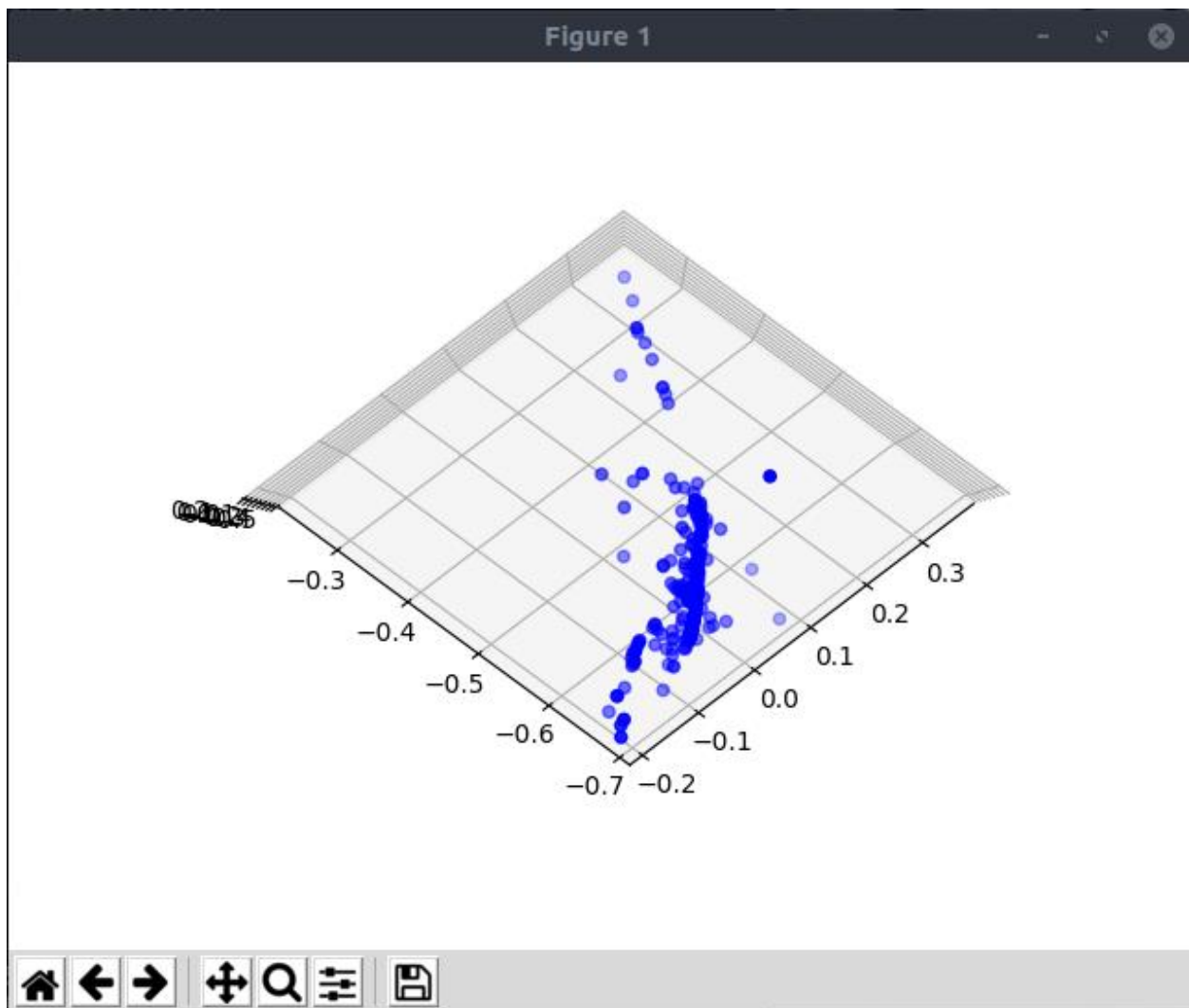
Original Images boba1.jpg and boba2.jpg



Problem 1: Point Matching

```
PROBLEMS OUTPUT DEBUG CONSOLE TERMINAL
xxkanade@xxkanade-VirtualBox:~$ cd Documents/rcv/hw6
xxkanade@xxkanade-VirtualBox:~/Documents/rcv/hw6$ python hw6.py
Fundamental Matrix
[[ 1.98490393e-08  3.46216107e-07 -4.92687165e-04]
 [ 7.46346517e-08  3.85043431e-08 -2.26107232e-03]
 [-1.65033258e-05  1.53777212e-03  1.00000000e+00]]
Essential Matrix
[[ 0.17085131  2.88978376  0.05224554]
 [ 0.62295774  0.31164994 -6.03673613]
 [ 0.3264223   5.64996639  0.17830047]]
Right Camera Matrix
[[ 2.93386019e+03  0.00000000e+00  1.13775712e+03  0.00000000e+00]
 [ 0.00000000e+00  2.84497637e+03  1.40926881e+03  0.00000000e+00]
 [ 0.00000000e+00  0.00000000e+00  1.00000000e+00  0.00000000e+00]]
Left Camera Matrix
[[ 1.75011747e+03 -2.51798692e+03 -7.06298504e+02 -2.09456542e+03]
 [ 1.88828791e+03 -4.01713725e+01  2.55199611e+03  6.57684023e+02]
 [ 9.55302617e-01  2.54378650e-01 -1.50626732e-01  4.55105524e-01]]
```

Problem 2 & 3: Fundamental, Essential, and Camera Matrices



Problem 4: Boba Tea Point Cloud