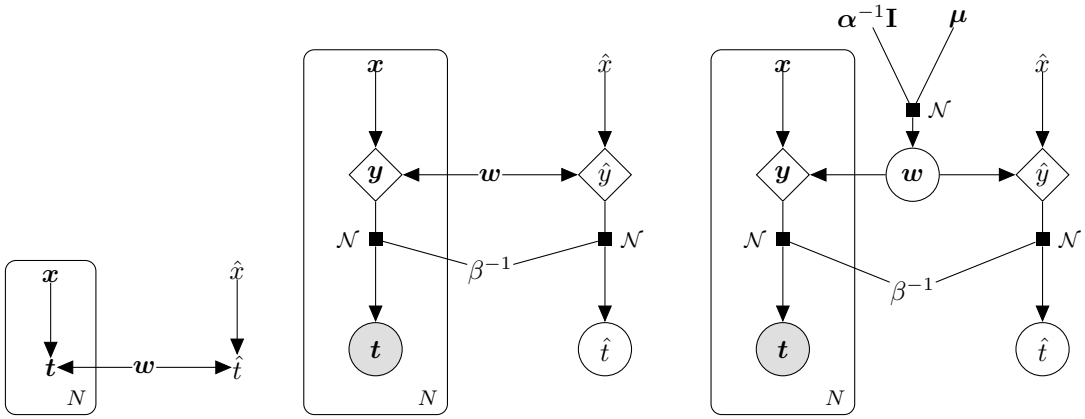
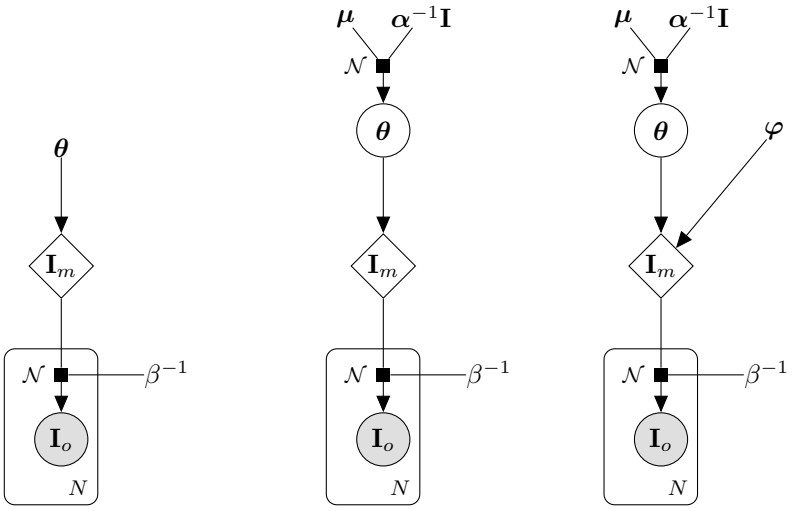


(a). LSE (b) MLE (c) MAP & Full Bayesian

Figure 1: Polynomial curve fitting models in PRML: (a) Least Square Estimation in \$1.1; (b) Maximum Likelihood Estimation (point estimation) in \$2.5; (c) Maximum-a-Posteriori estimation (point estimation) in \$2.5 and full bayesian approach in \$2.6



(a) Under Glass (MLE) (b) Under Glass (MAP) (c) FOD

Figure 2: MAPIS models: $\boldsymbol{\theta} = \{\text{pitch}, \text{angle}, \text{tlx}, \text{tly}\}$, $\alpha^{-1}\mathbf{I}$ is the covariance matrix for $\boldsymbol{\theta}$; $\mathbf{I}_m$ is the image generated by the model (it's supposed that the number of columns and rows of pinholes are known); $\mathbf{I}_o$ are captured images by sensor; β^{-1} is the variance of Gaussian noise added to each pixel of $\mathbf{I}_m$ (due to sensor noise and other effects). (a) MLE point estimation for $\boldsymbol{\theta}$; (b) MAP point estimation for $\boldsymbol{\theta}$; (c) Adding $\boldsymbol{\varphi} = \{?\}$ as the cause for biased noise due to reflections...