VVV2013 – group task
Structure from motion (SFM)

Design, develop and implement robust camera position estimation for the computation of disparity map.

- Feature extraction and matching in real time (gpu)
- Epipolar computation (fundamental matrix)
- Estimate camera parameters
- Bundle adjustments

People involved: Sean Ryan Fanello, Vadim Tikhanoff, Riccardo Spica (in theory)