⑤ Translating origin point from $\boldsymbol{r}^{T}$ to O^{T}

⑥ Gram Schmidt Cartesian Coordinate Transformation on $\bar{\boldsymbol{x}}^{T}$, $\bar{\boldsymbol{y}}^{T}$, and $\bar{\boldsymbol{z}}^{T}$

O^{T} X^{T} Y^{T} Z^{T} $\bar{\boldsymbol{x}}^{T}$ $\bar{\boldsymbol{y}}^{T}$ $\bar{\boldsymbol{z}}^{T}$

④ Triangulation

④ Triangulation

D^{T}

③ Projecting

X^{C1} Y^{C1} D^{C1} Z^{C1}

O^{I1} U^{I1} V^{I1} D^{I1} (u^{x1}, v^{x1})

⑦ Rotating arrow points in D^{T} in order to fit D^{H}

D^{H}

Z^{H} Y^{H} X^{H} $O^{H(C1,C2)}\boldsymbol{r}^{T}$ $z^{H(C1,C2,T)}$ $y^{H(C1,C2,T)}$ $x^{H(C1,C2,T)}$

O^{I2} U^{I2} V^{I2} D^{I2} (u^{x2}, v^{x2})

D^{C2} X^{C2} Y^{C2} Z^{C2}

③ Projecting

① Obtaining origin points: O^{C1-CN} each camera

② Obtaining Rvec and tvec each camera for projecting