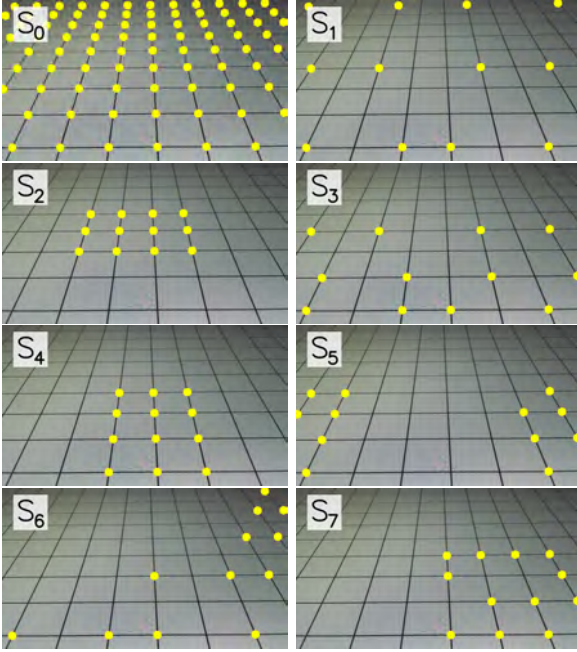
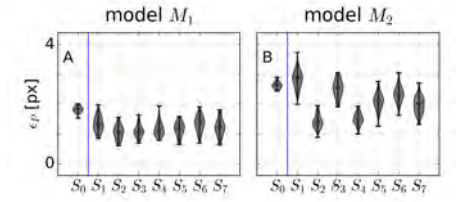


# Camera 1, 12 GCPs and angle $A_1$

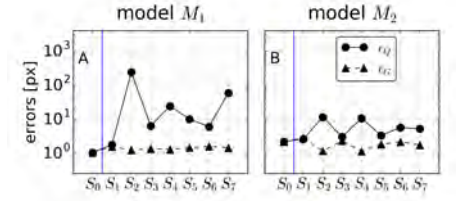
Sets of points



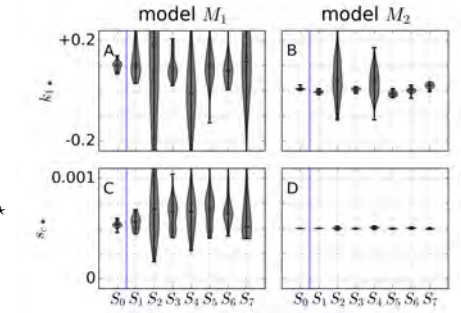
Errors  $\epsilon_P$



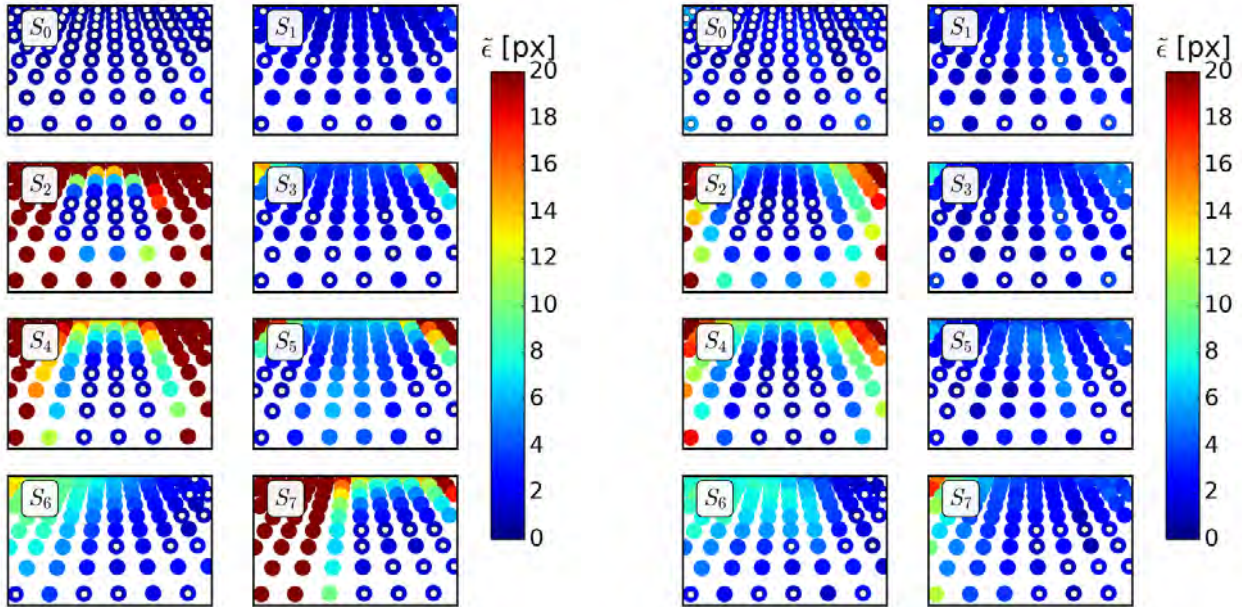
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$

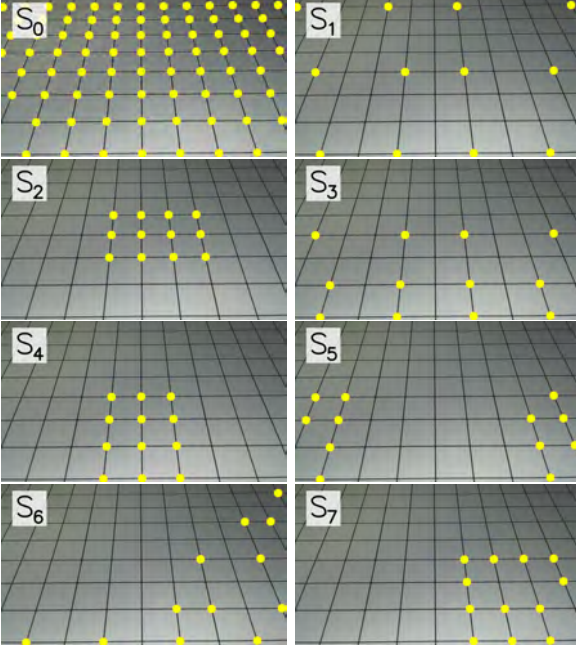


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

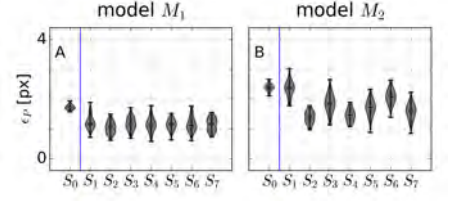


## Camera 1, 12 GCPs and angle $A_2$

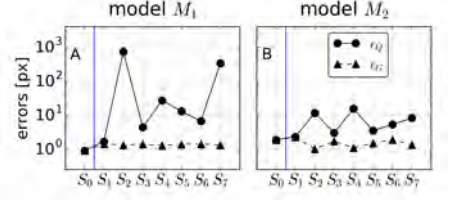
Sets of points



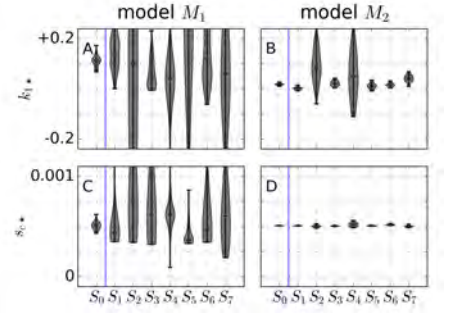
Errors  $\epsilon_P$



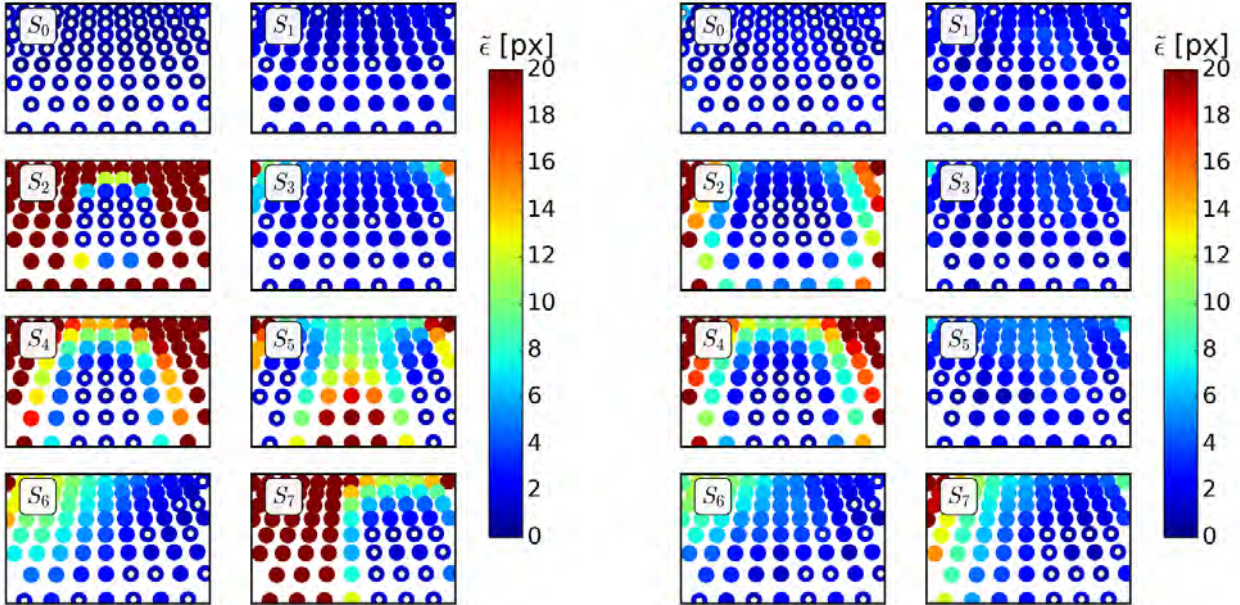
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$



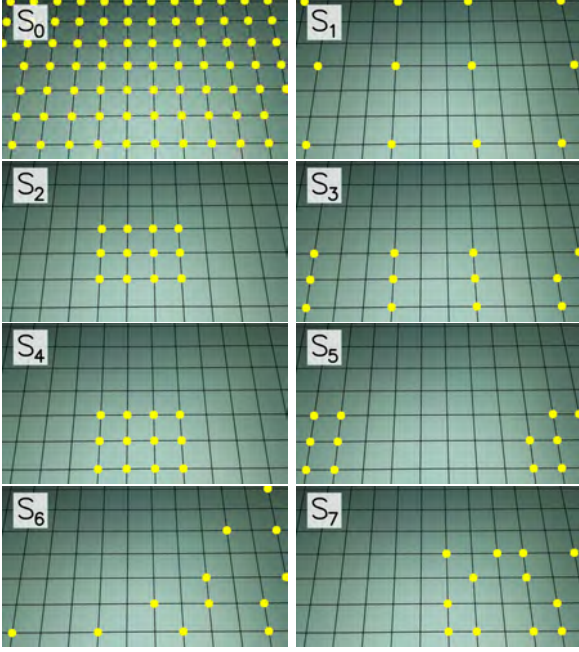
Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)



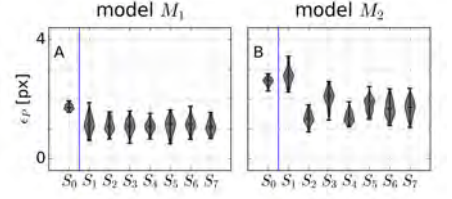


# Camera 1, 12 GCPs and angle $A_3$

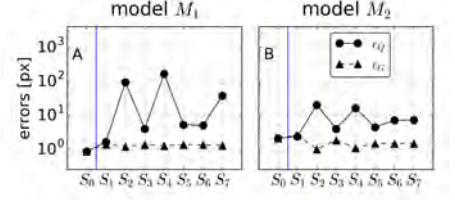
Sets of points



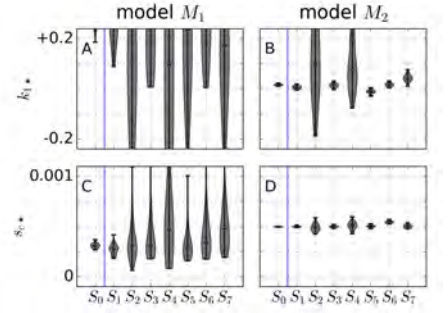
Errors  $\epsilon_P$



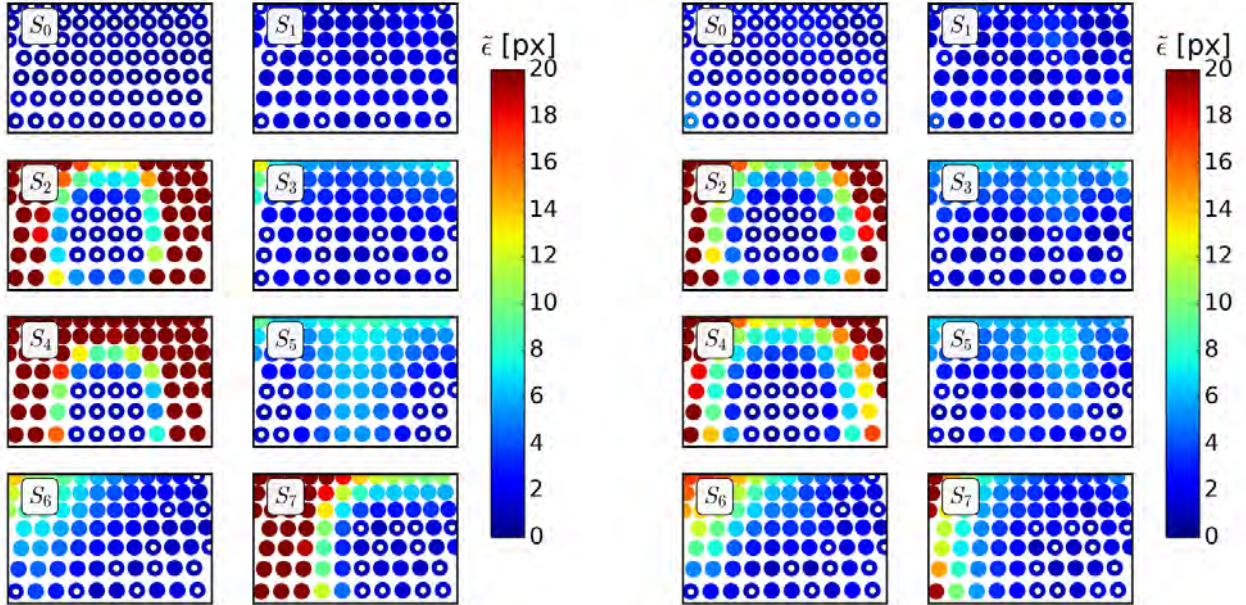
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$

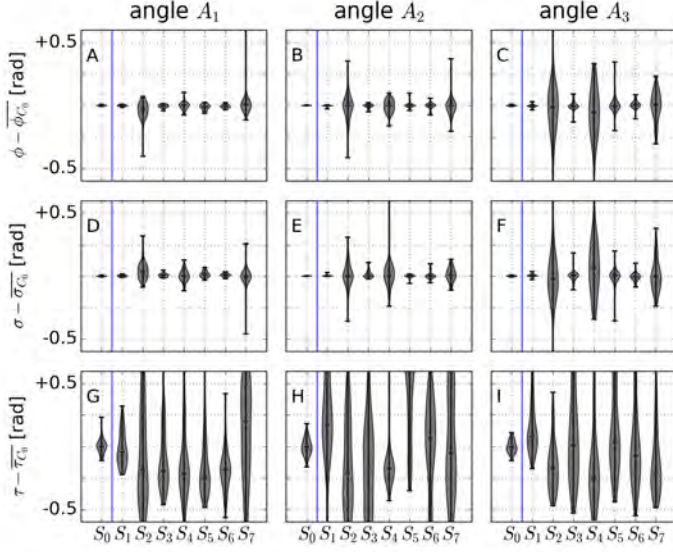


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

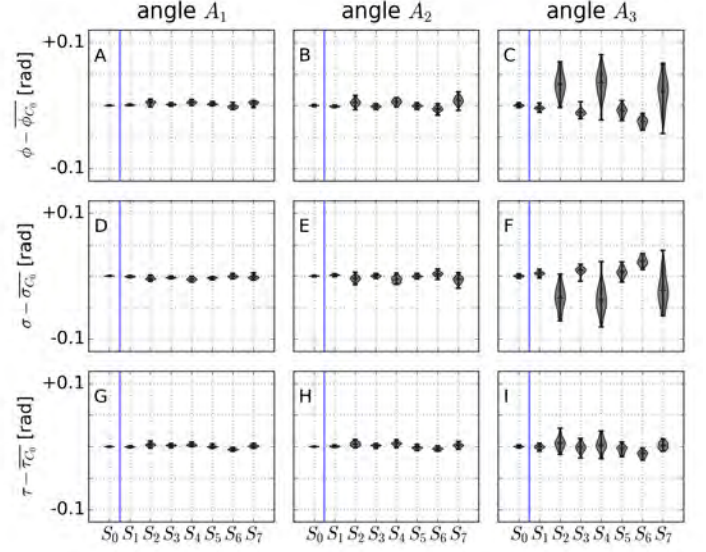


## Camera 1, 12 GCPs ( $A_1$ , $A_2$ and $A_3$ )

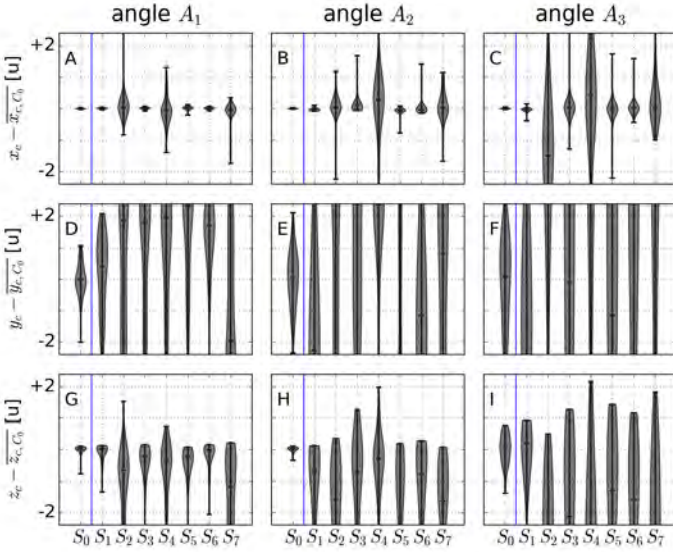
Extrinsic: eulerian angles for  $M_1$



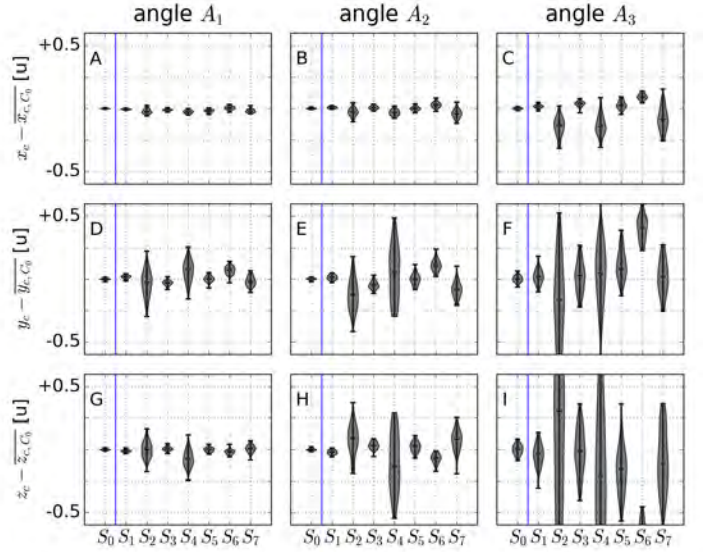
Extrinsic: eulerian angles for  $M_2$



Extrinsic: camera position for  $M_1$



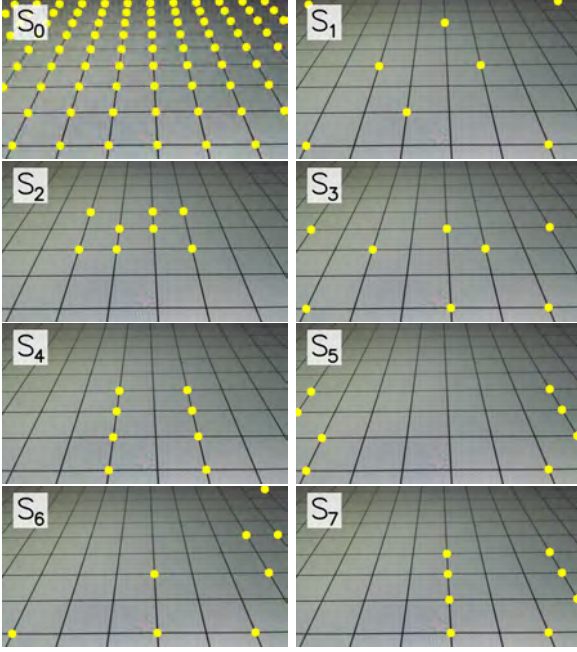
Extrinsic: camera position for  $M_2$



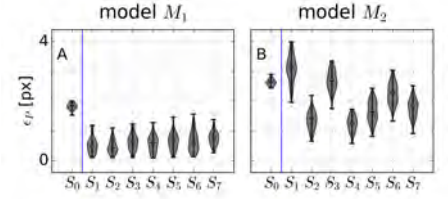


## Camera 1, 8 GCPs and angle $A_1$

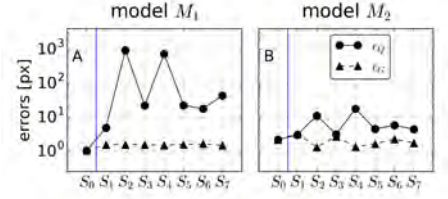
Sets of points



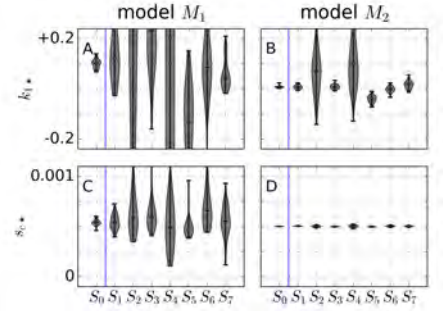
Errors  $\epsilon_P$



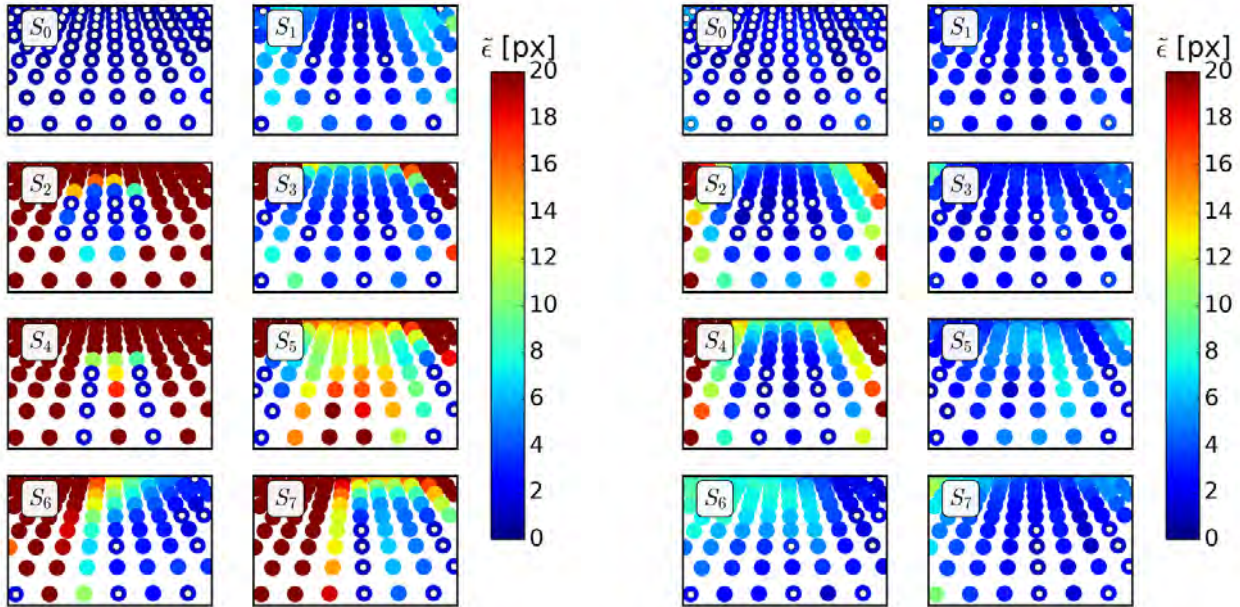
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$

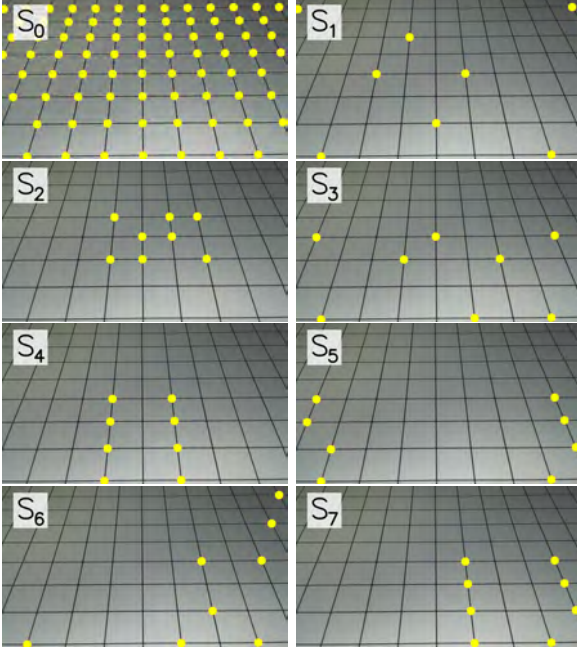


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

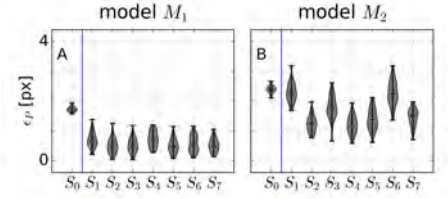


## Camera 1, 8 GCPs and angle $A_2$

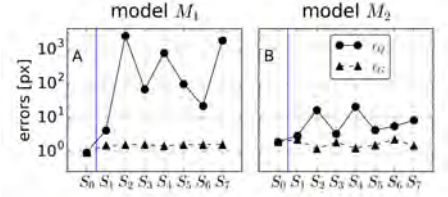
Sets of points



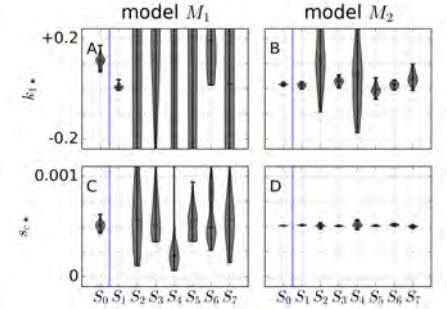
Errors  $\epsilon_P$



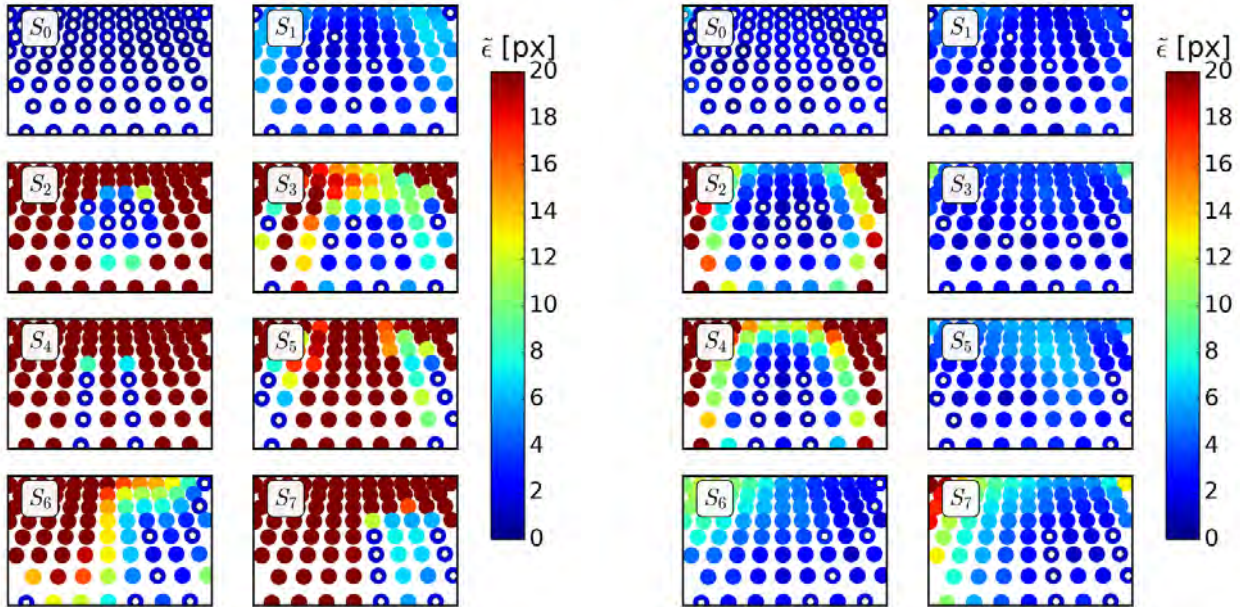
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$



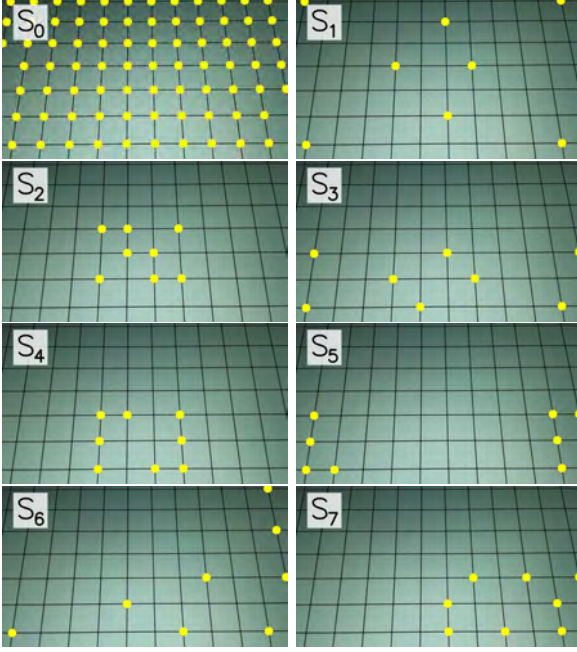
Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)



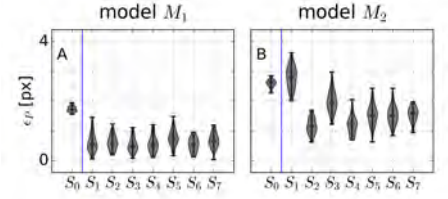


## Camera 1, 8 GCPs and angle $A_3$

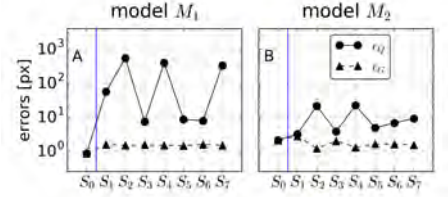
Sets of points



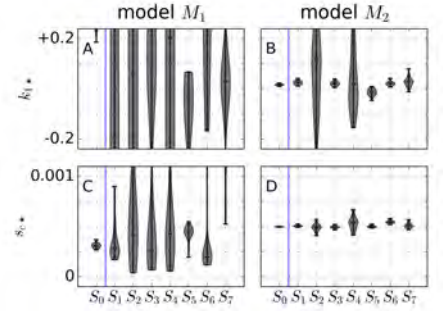
Errors  $\epsilon_P$



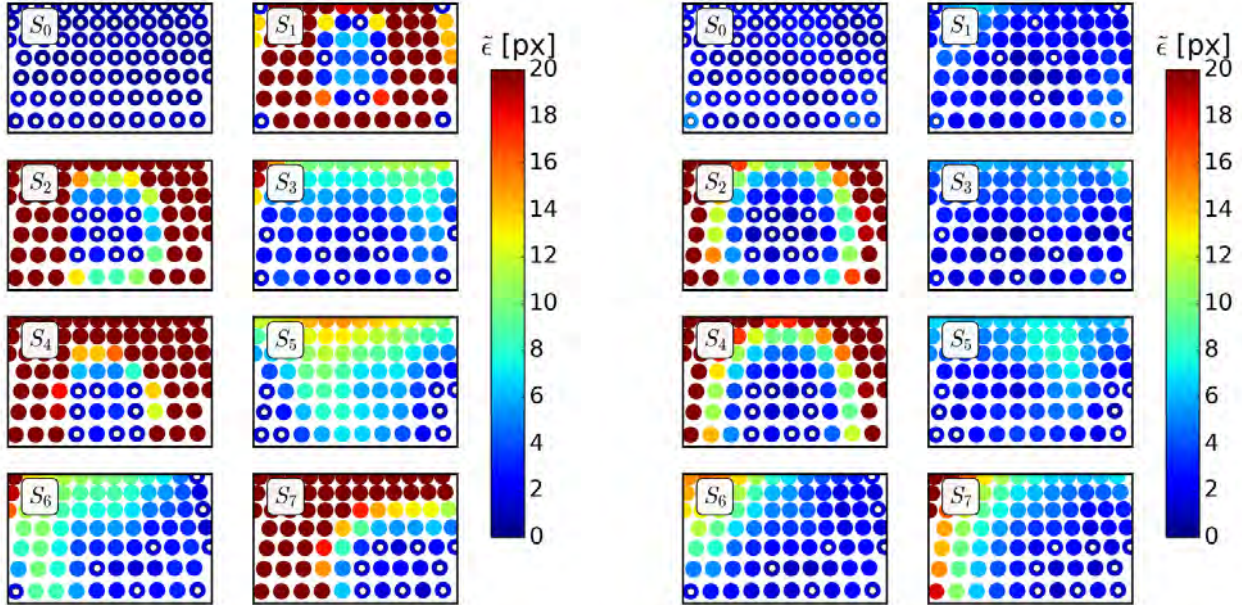
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$

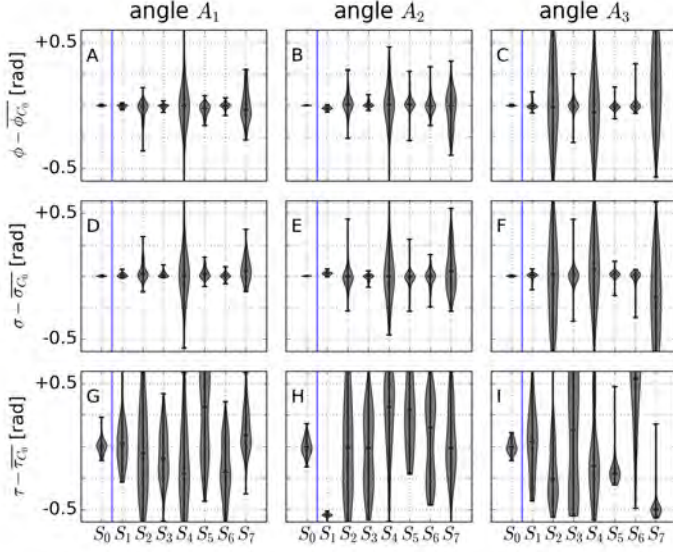


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

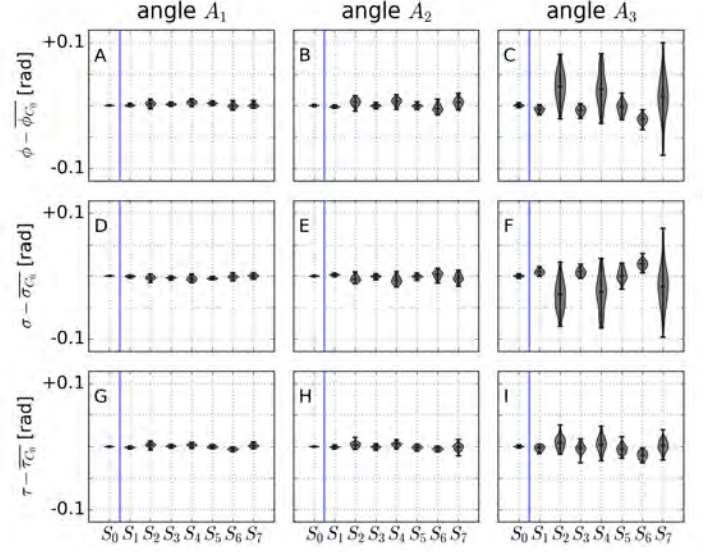


## Camera 1, 8 GCPs ( $A_1$ , $A_2$ and $A_3$ )

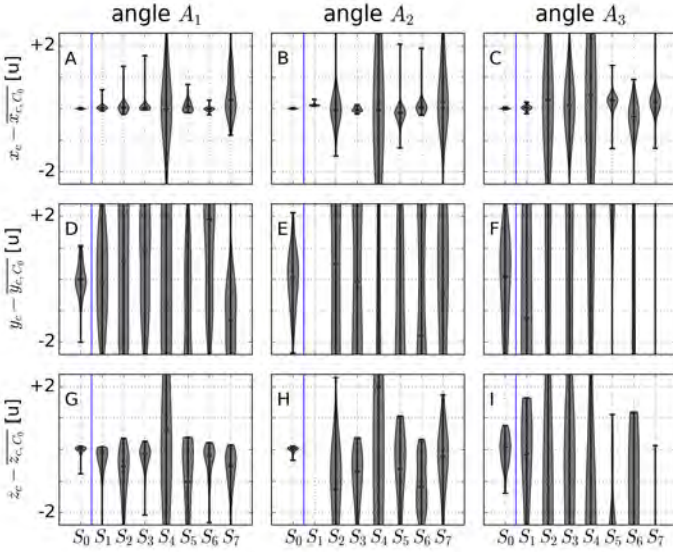
Extrinsic: eulerian angles for  $M_1$



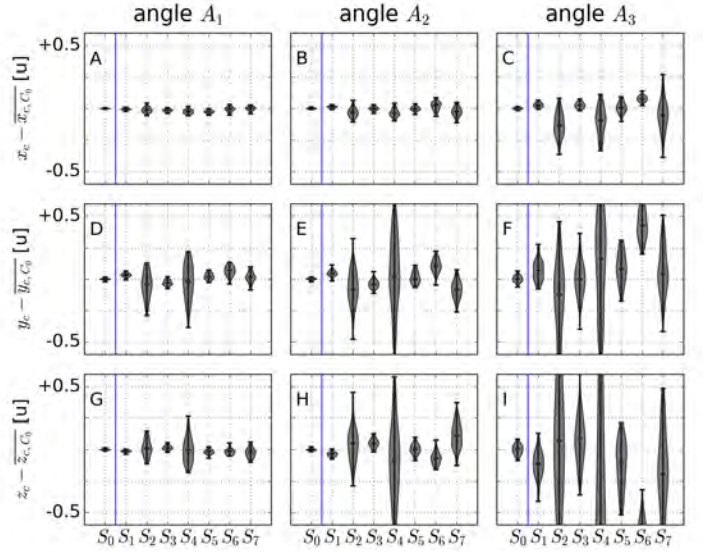
Extrinsic: eulerian angles for  $M_2$



Extrinsic: camera position for  $M_1$



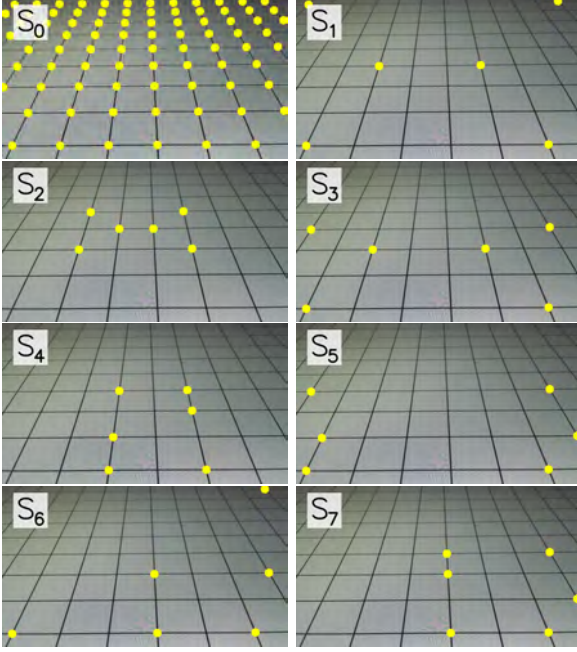
Extrinsic: camera position for  $M_2$



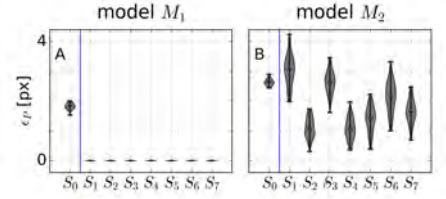


## Camera 1, 6 GCPs and angle $A_1$

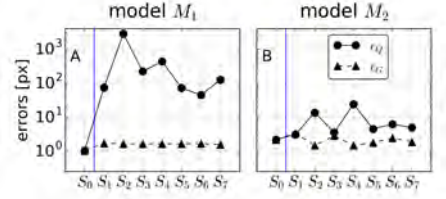
Sets of points



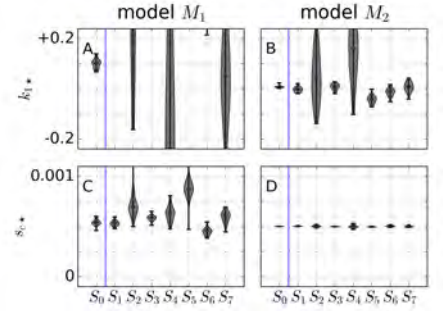
Errors  $\epsilon_P$



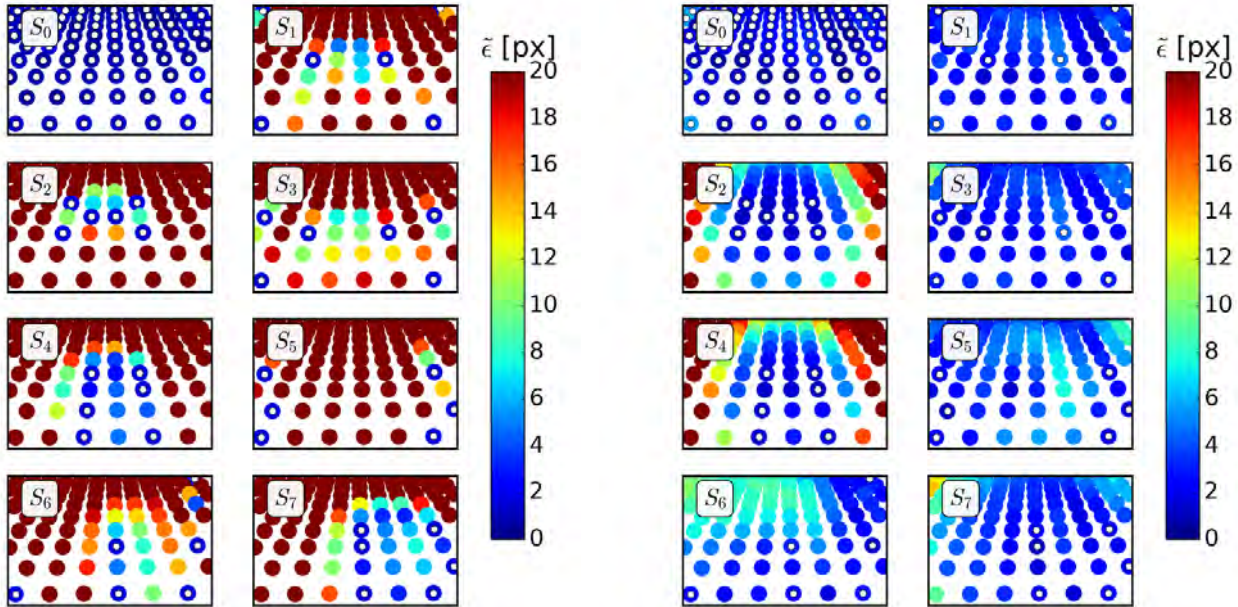
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$

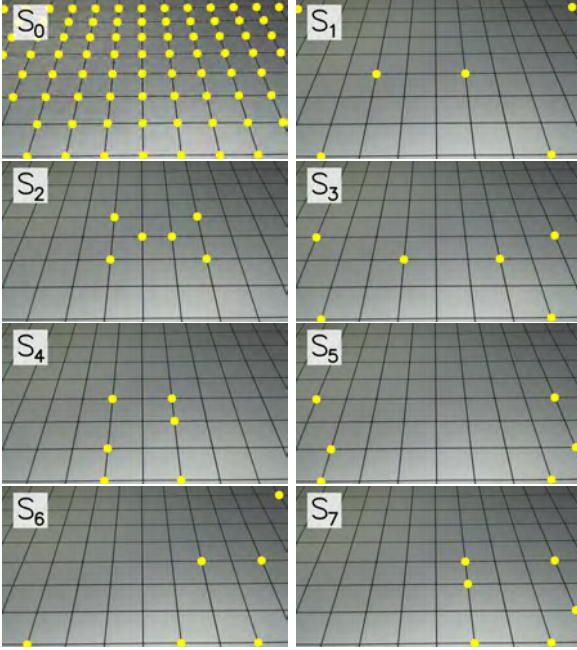


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

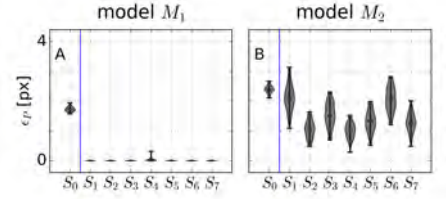


## Camera 1, 6 GCPs and angle $A_2$

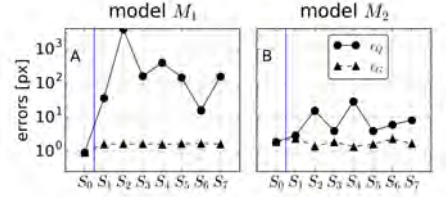
Sets of points



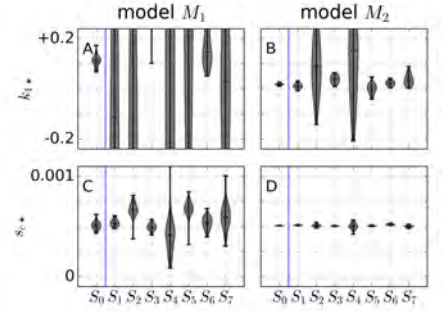
Errors  $\epsilon_P$



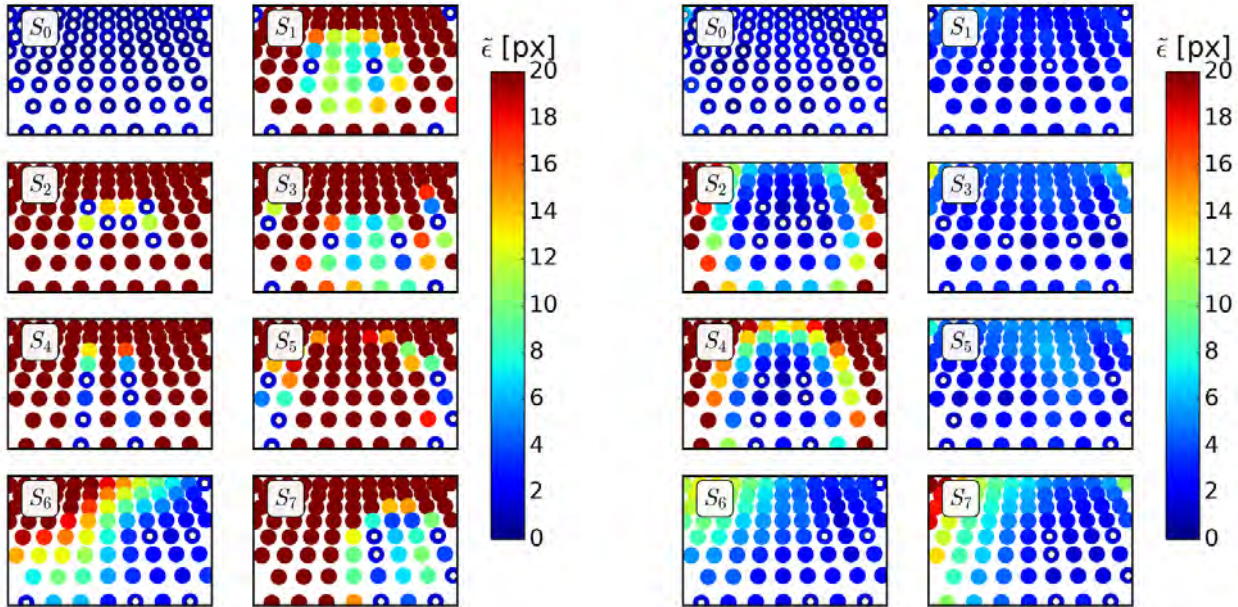
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$



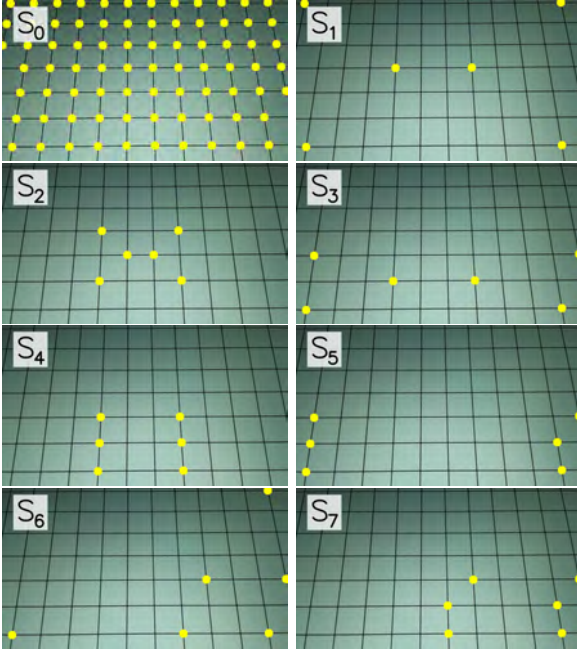
Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)



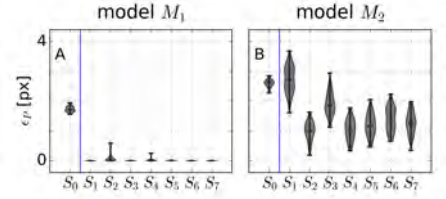


## Camera 1, 6 GCPs and angle $A_3$

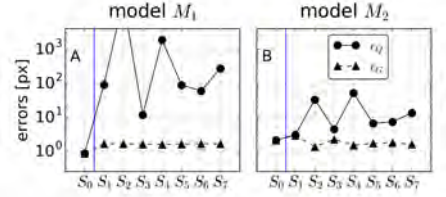
Sets of points



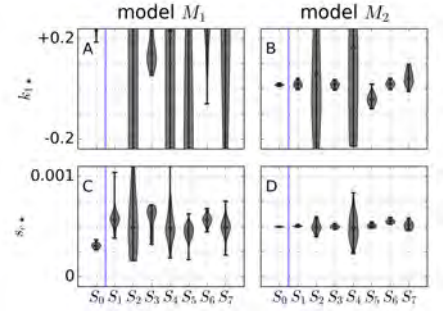
Errors  $\epsilon_P$



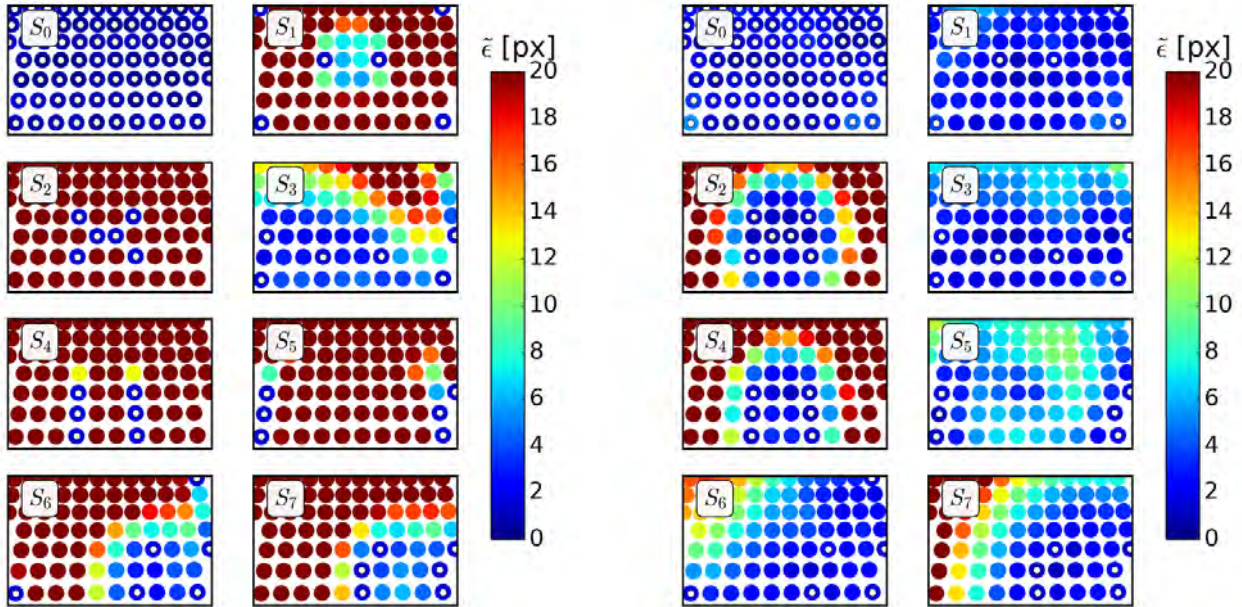
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$

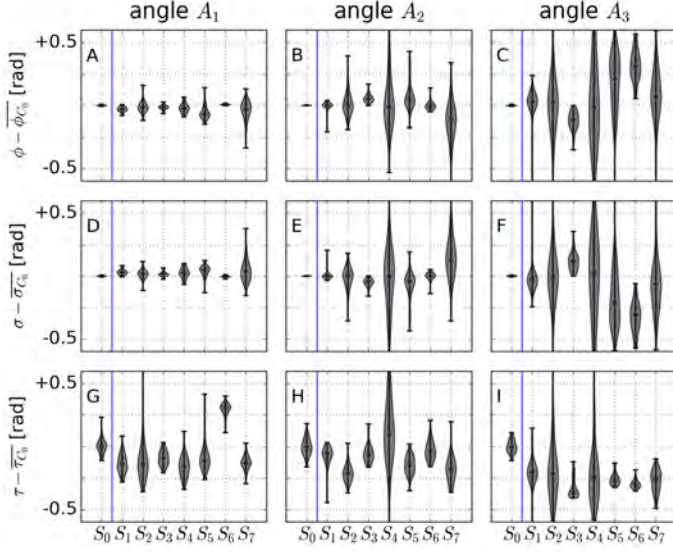


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

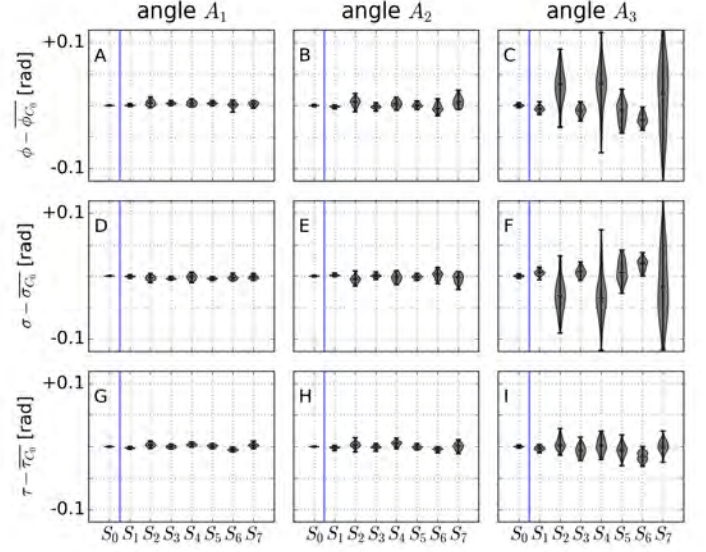


## Camera 1, 6 GCPs ( $A_1$ , $A_2$ and $A_3$ )

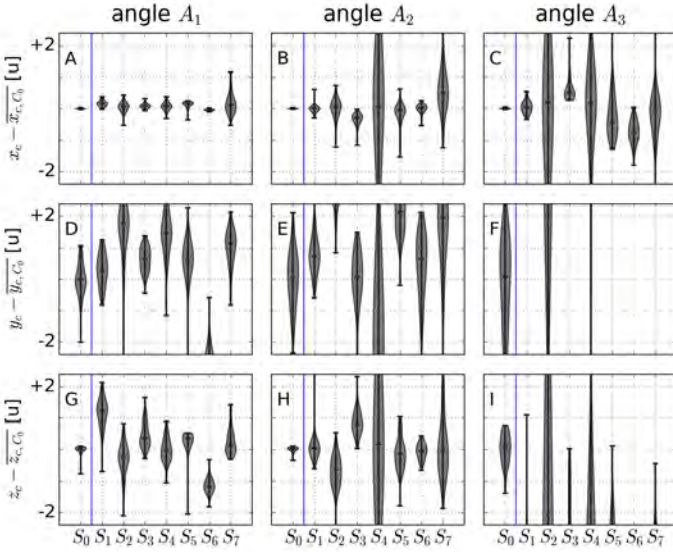
Extrinsic: eulerian angles for  $M_1$



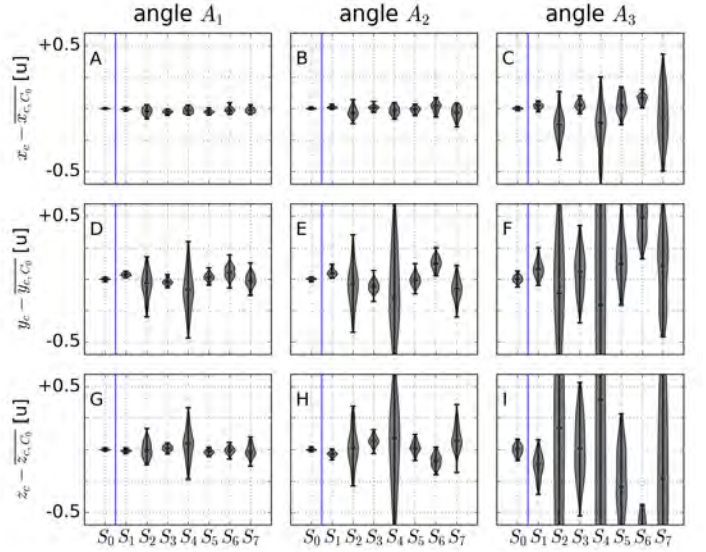
Extrinsic: eulerian angles for  $M_2$



Extrinsic: camera position for  $M_1$



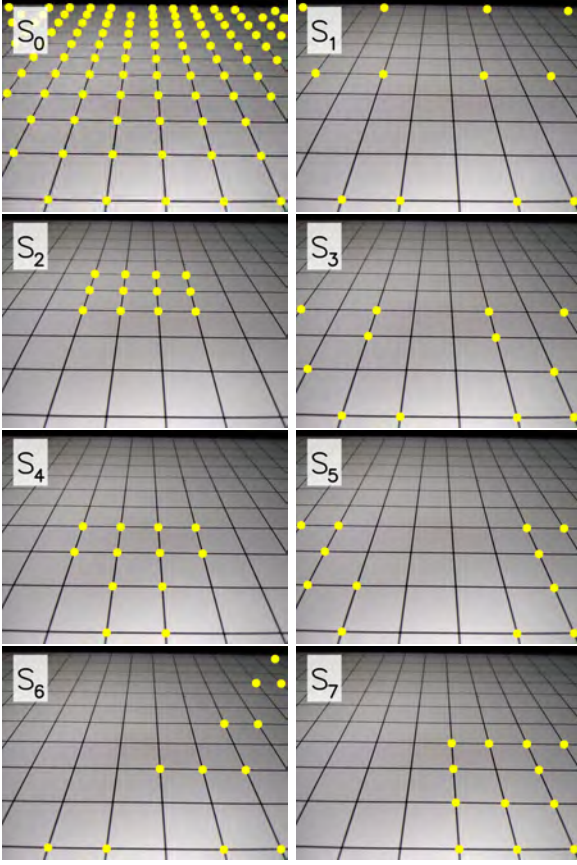
Extrinsic: camera position for  $M_2$



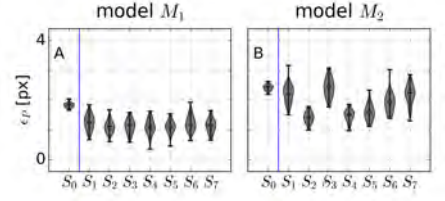


## Camera 2, 12 GCPs and angle $A_1$

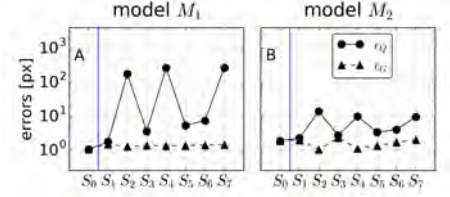
Sets of points



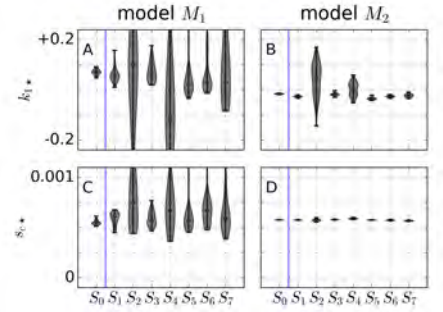
Errors  $\epsilon_P$



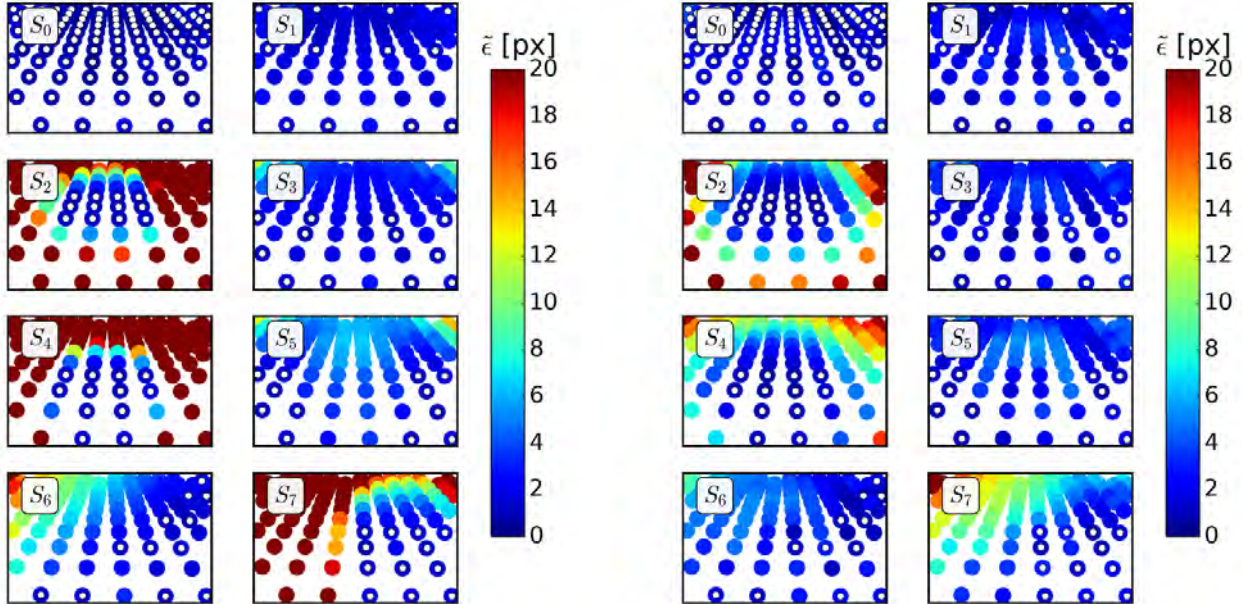
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1*}$  and  $s_{c*}$



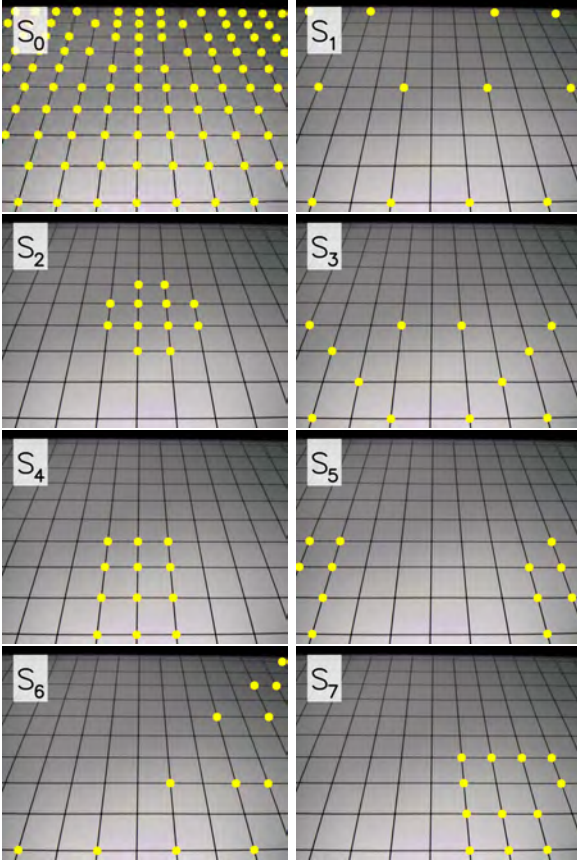
Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)



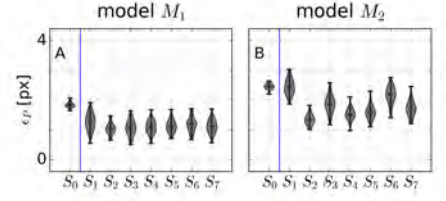


## Camera 2, 12 GCPs and angle $A_2$

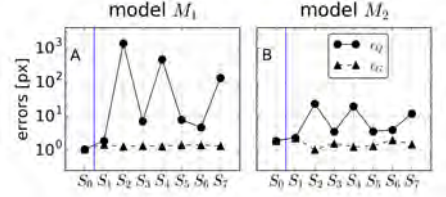
Sets of points



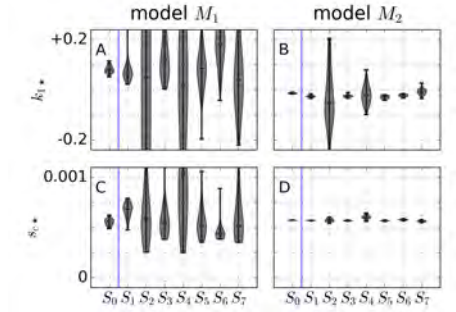
Errors  $\epsilon_P$



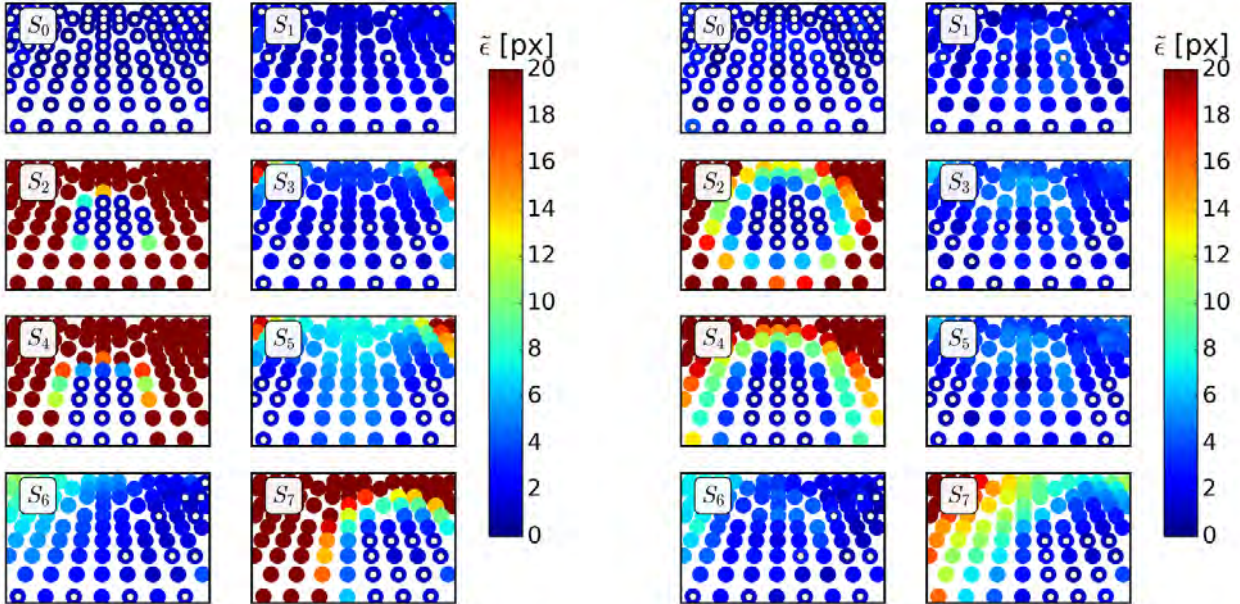
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1*}$  and  $s_{c*}$



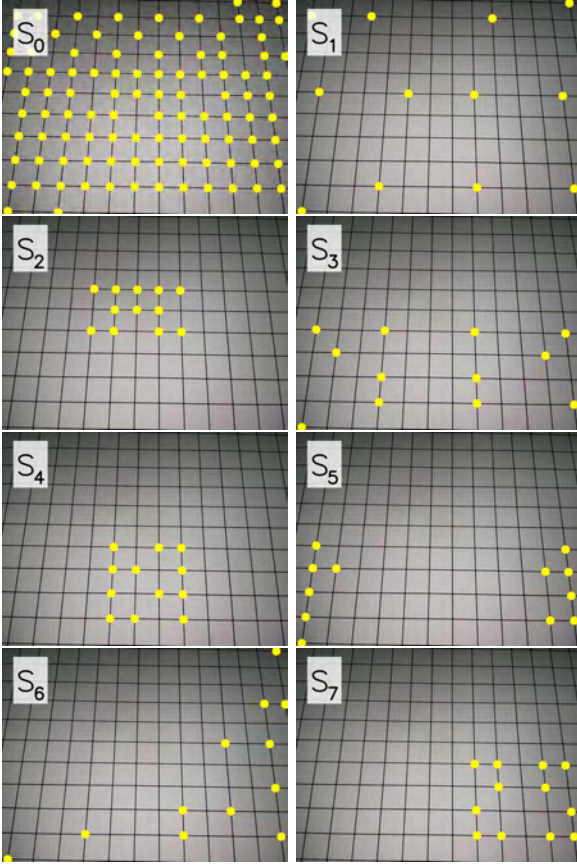
Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)



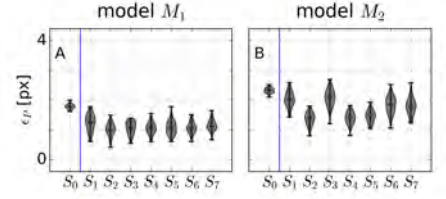


## Camera 2, 12 GCPs and angle $A_3$

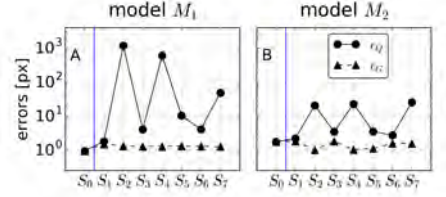
Sets of points



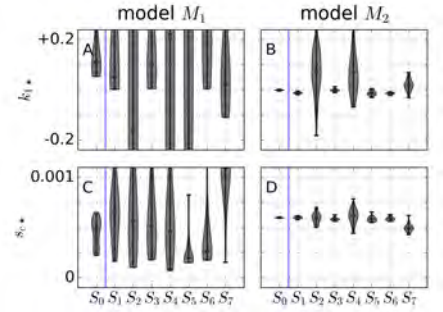
Errors  $\epsilon_P$



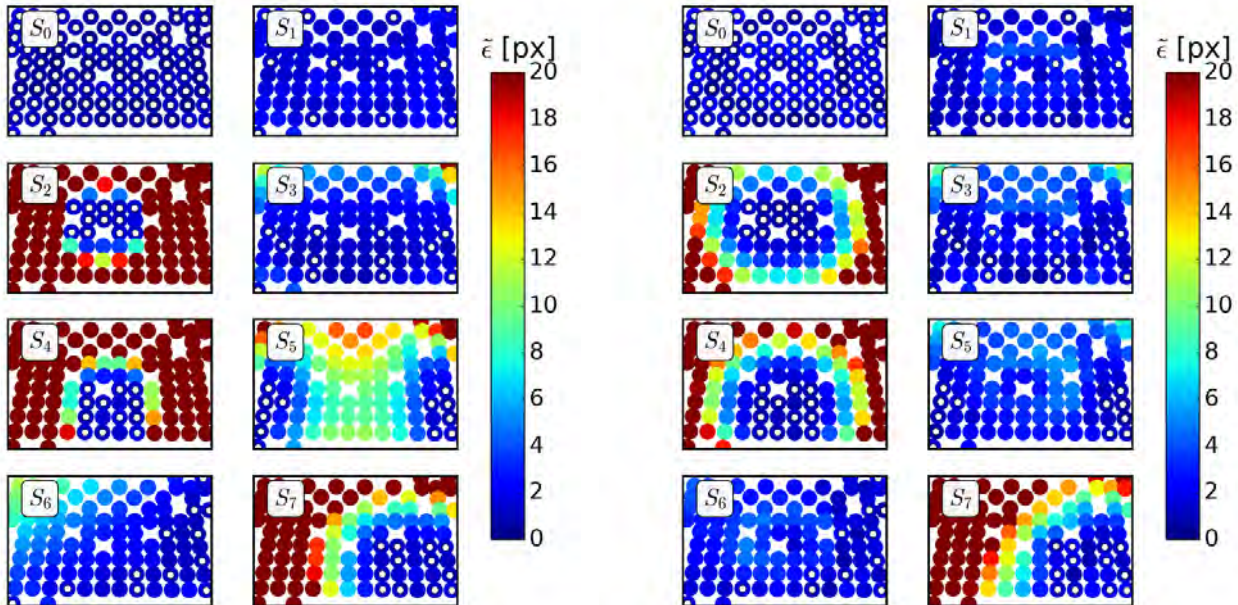
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1*}$  and  $s_{c*}$

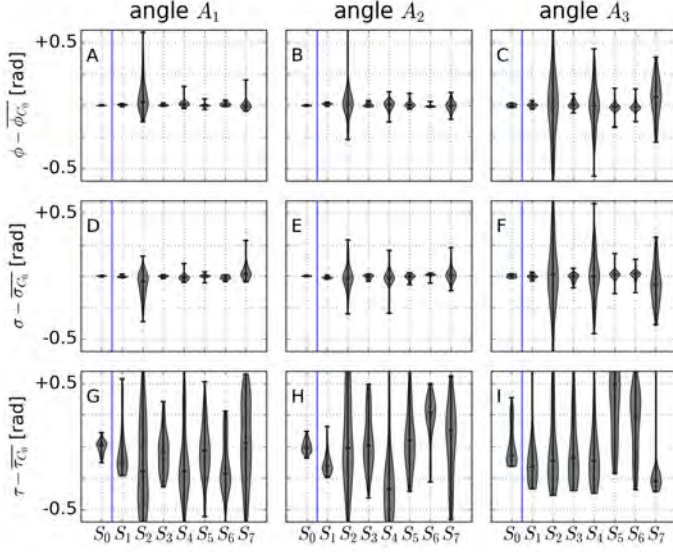


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

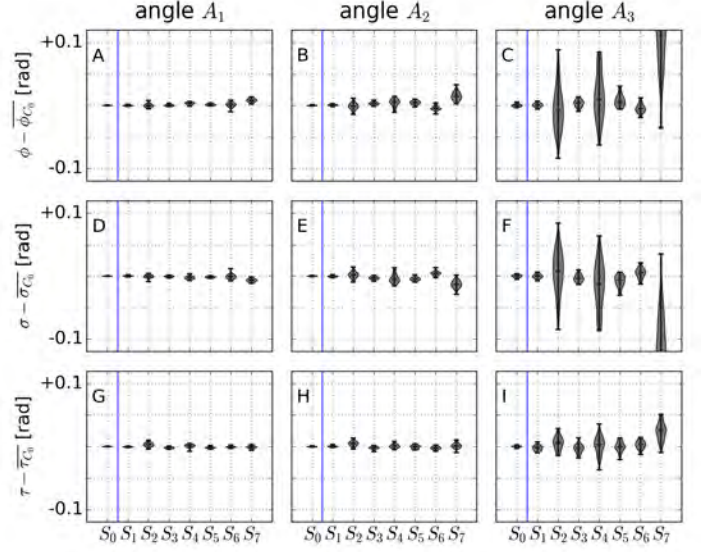


## Camera 2, 12 GCPs ( $A_1$ , $A_2$ and $A_3$ )

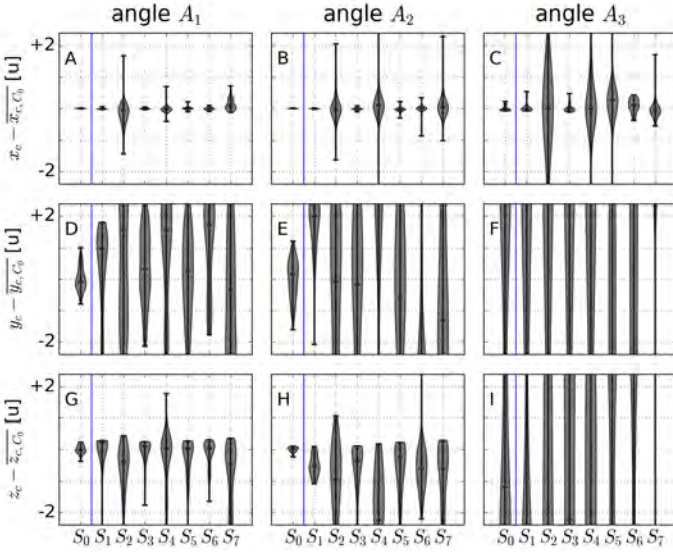
Extrinsic: eulerian angles for  $M_1$



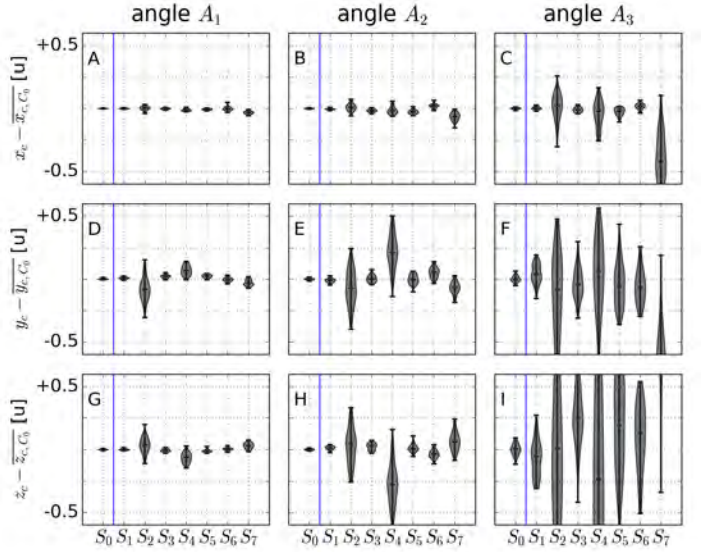
Extrinsic: eulerian angles for  $M_2$



Extrinsic: camera position for  $M_1$



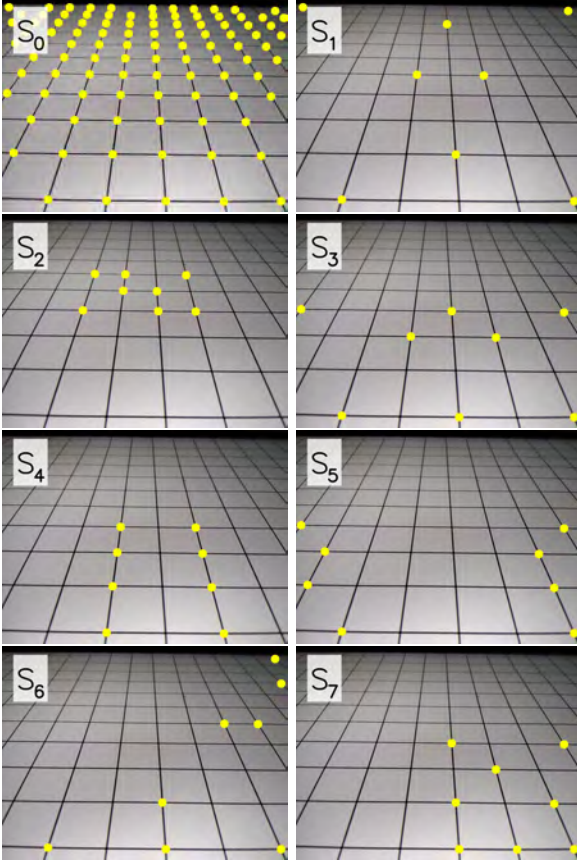
Extrinsic: camera position for  $M_2$



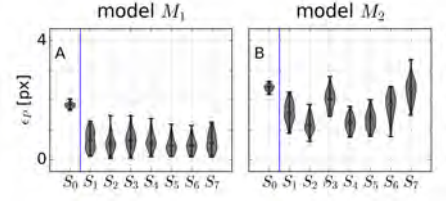


## Camera 2, 8 GCPs and angle $A_1$

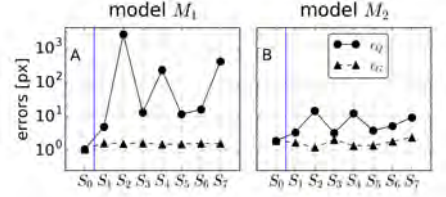
Sets of points



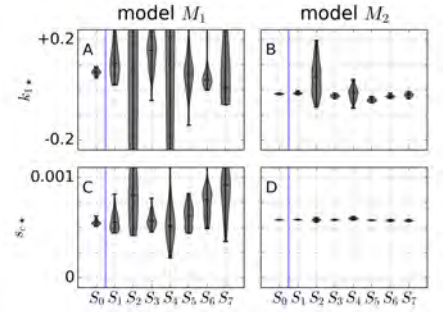
Errors  $\epsilon_P$



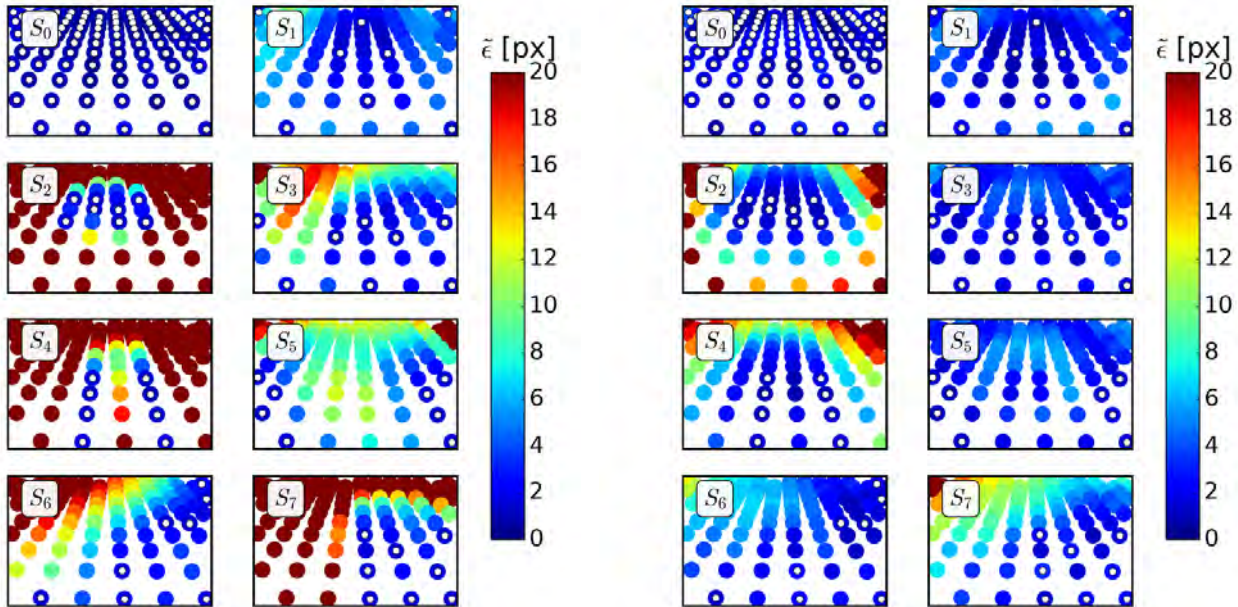
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1*}$  and  $s_{c*}$

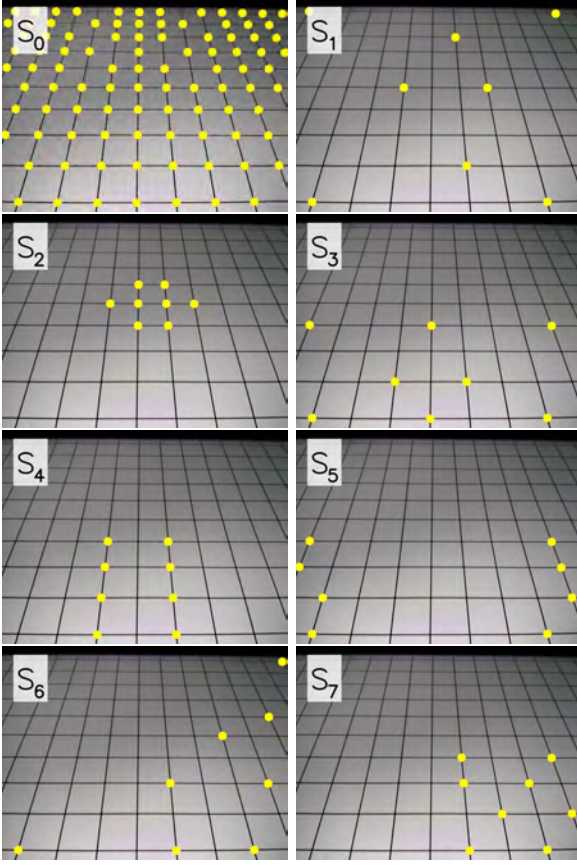


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

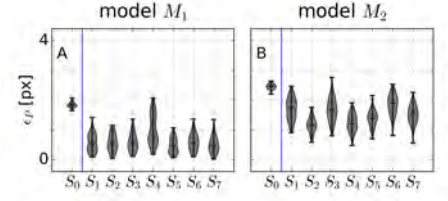


## Camera 2, 8 GCPs and angle $A_2$

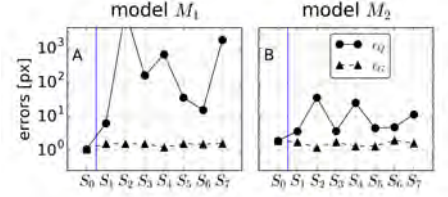
Sets of points



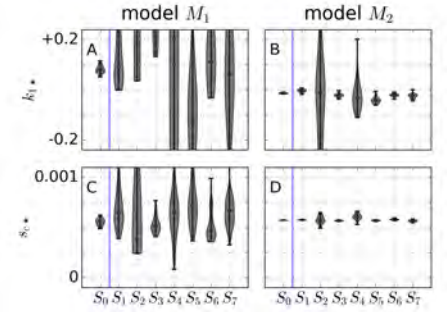
Errors  $\epsilon_P$



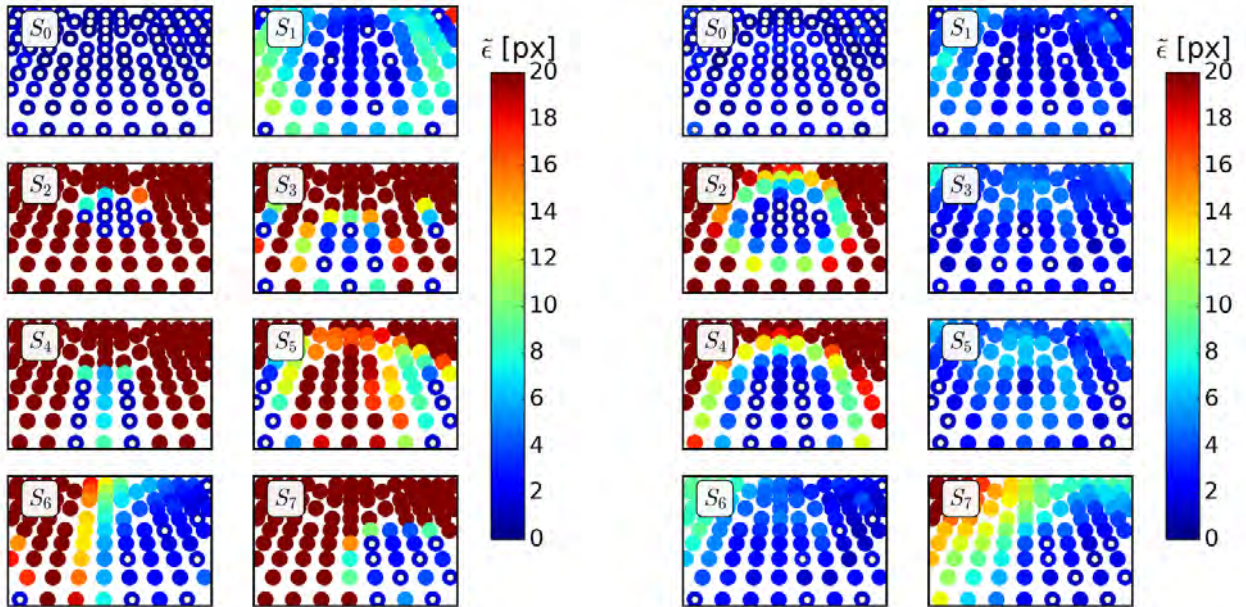
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1*}$  and  $s_{c*}$



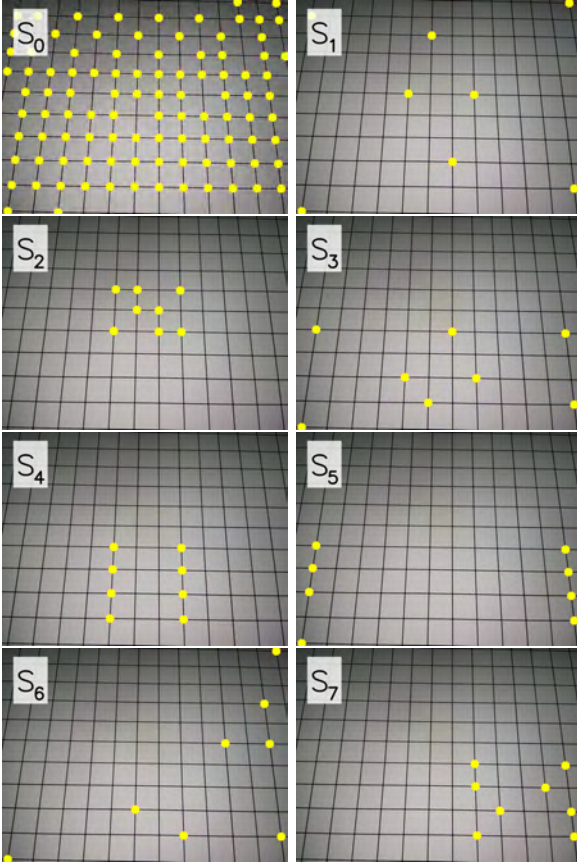
Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)



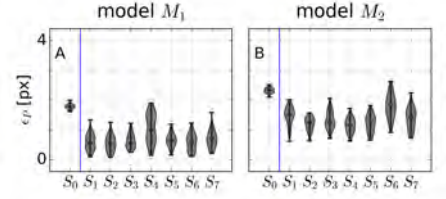


## Camera 2, 8 GCPs and angle $A_3$

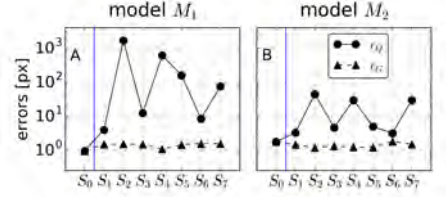
Sets of points



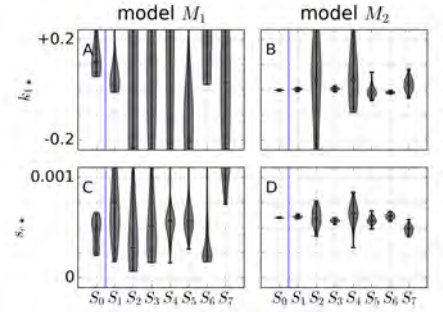
Errors  $\epsilon_P$



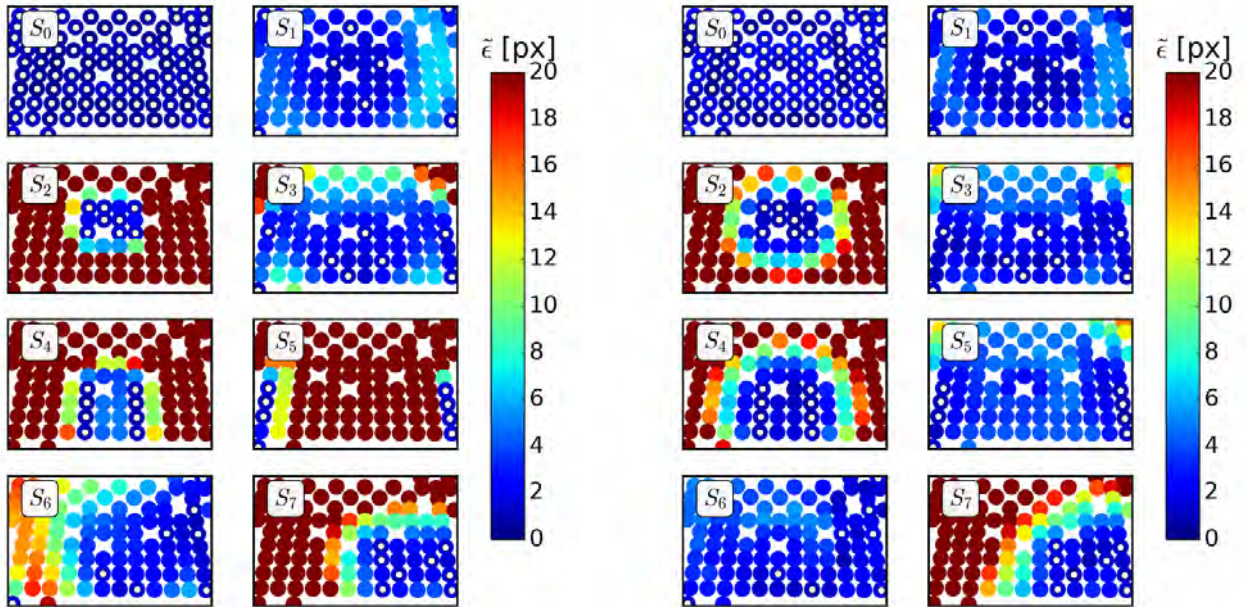
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1*}$  and  $s_{c*}$

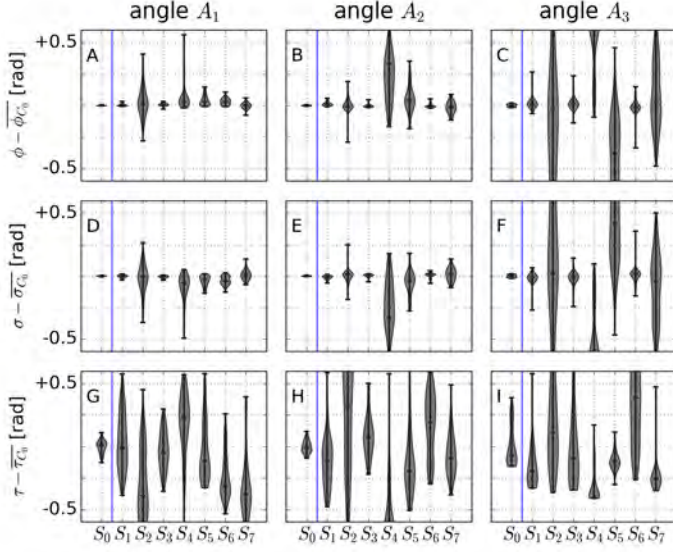


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

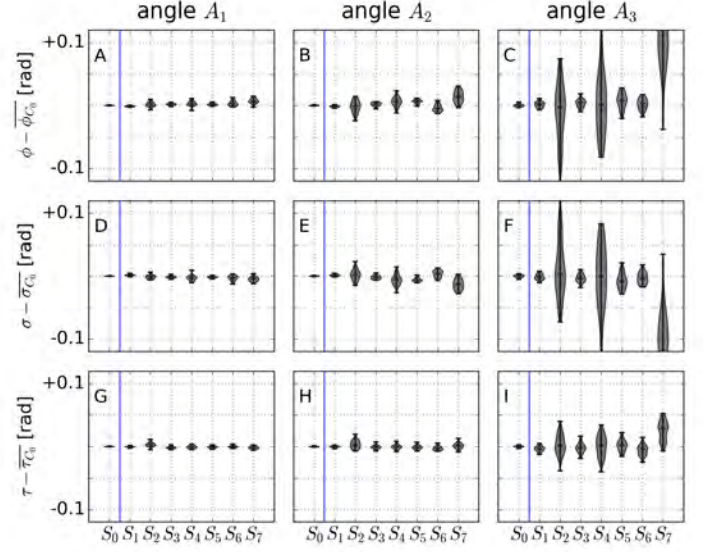


## Camera 2, 8 GCPs ( $A_1$ , $A_2$ and $A_3$ )

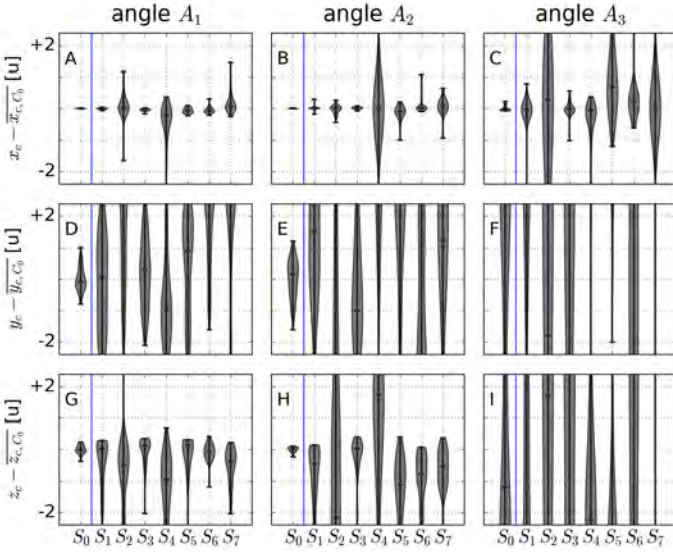
Extrinsic: eulerian angles for  $M_1$



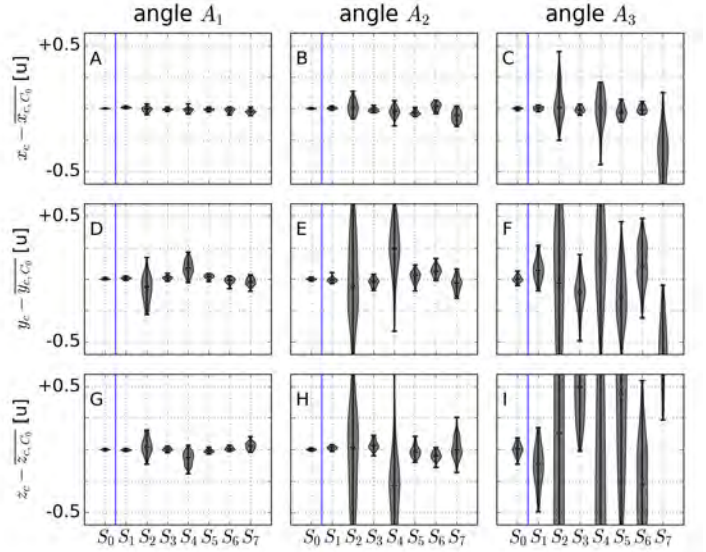
Extrinsic: eulerian angles for  $M_2$



Extrinsic: camera position for  $M_1$



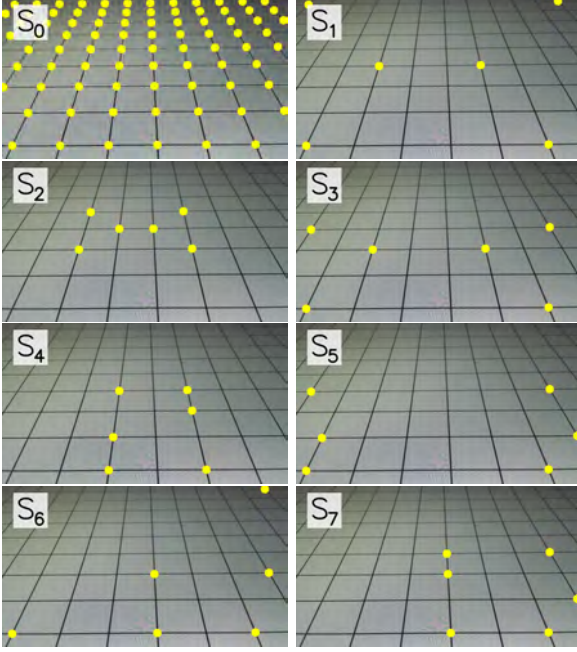
Extrinsic: camera position for  $M_2$



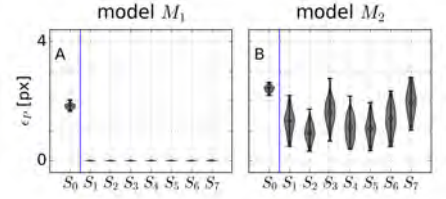


## Camera 2, 6 GCPs and angle $A_1$

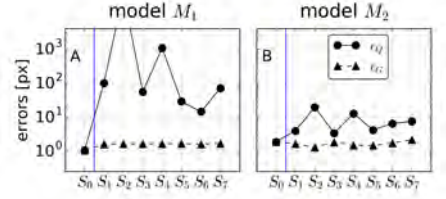
Sets of points



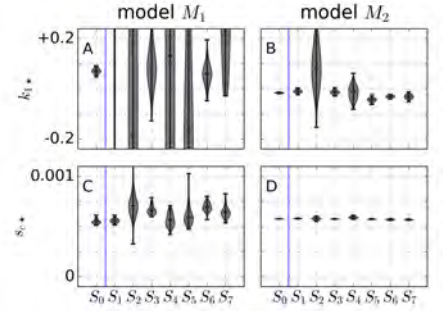
Errors  $\epsilon_P$



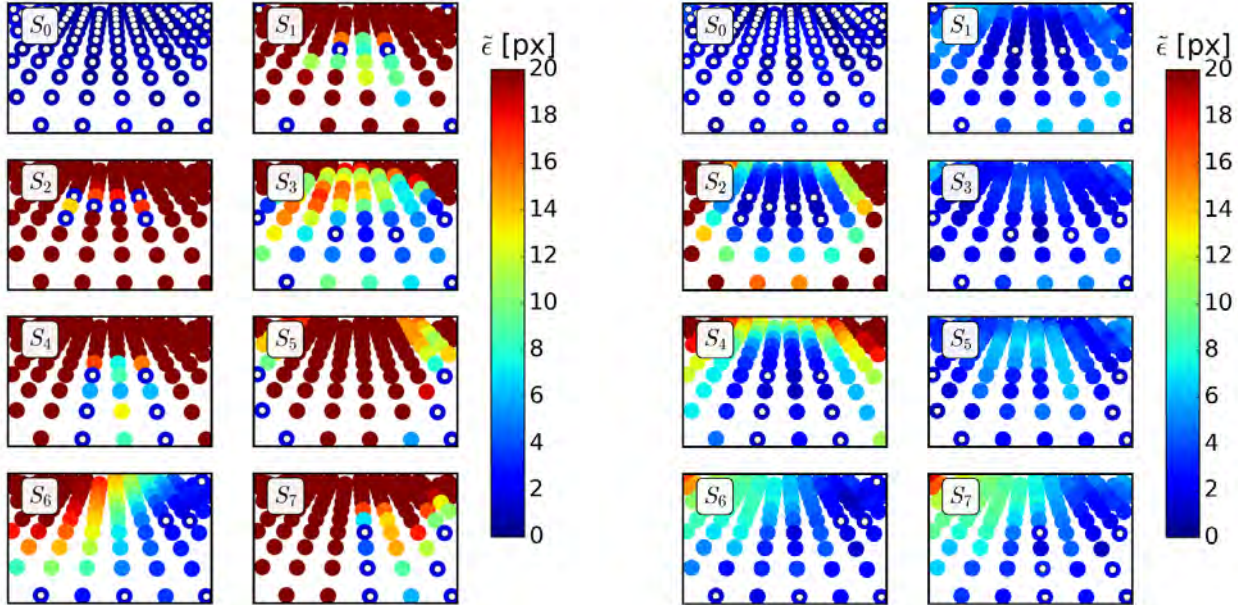
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1\star}$  and  $s_{c\star}$

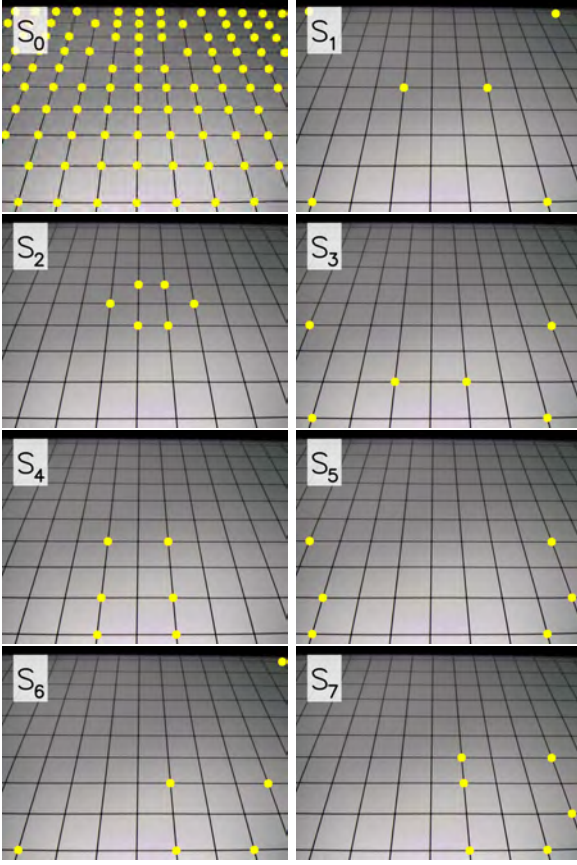


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

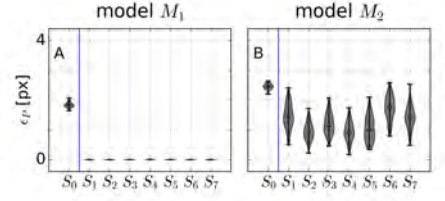


## Camera 2, 6 GCPs and angle $A_2$

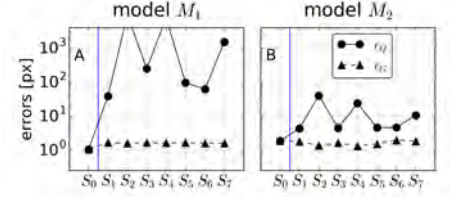
Sets of points



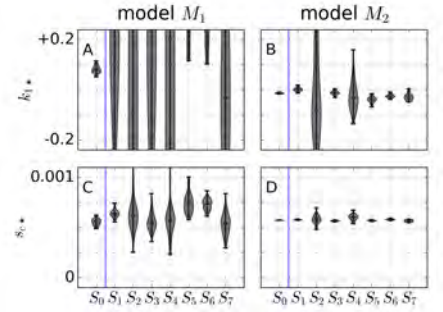
Errors  $\epsilon_P$



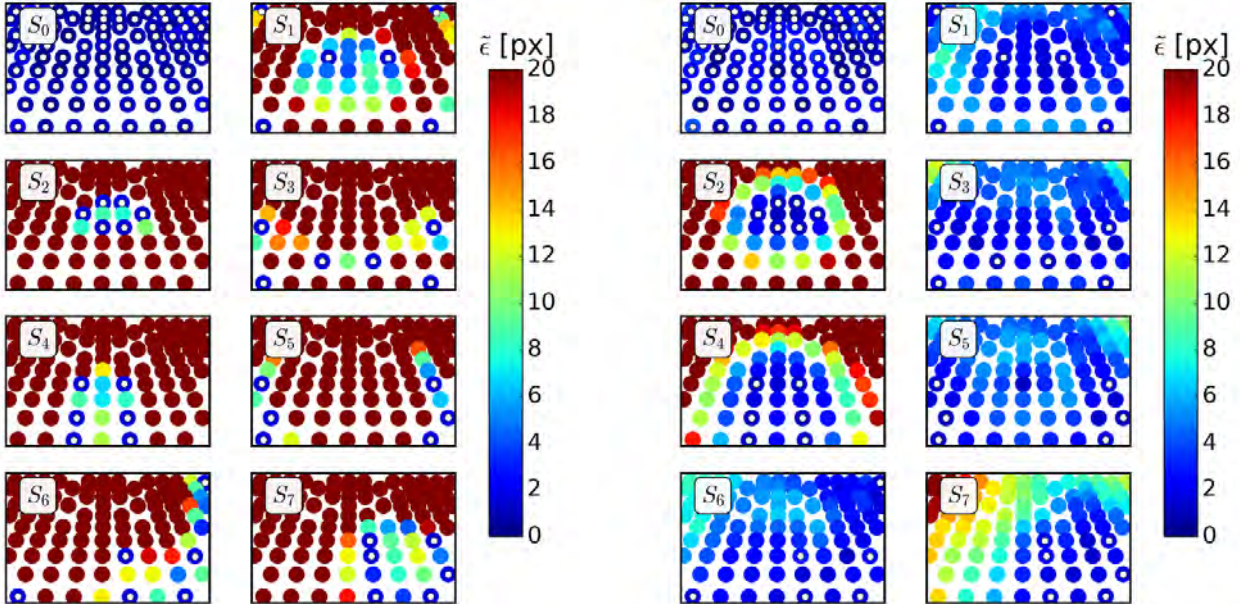
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1*}$  and  $s_{c*}$



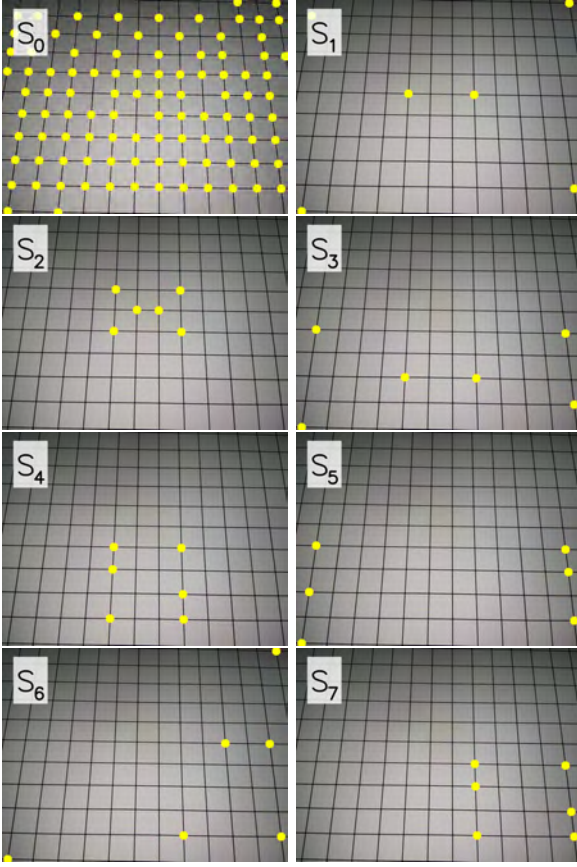
Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)



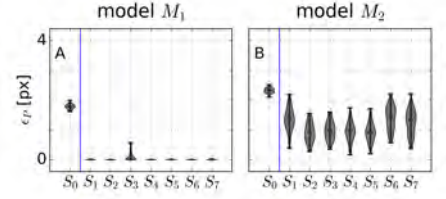


## Camera 2, 6 GCPs and angle $A_3$

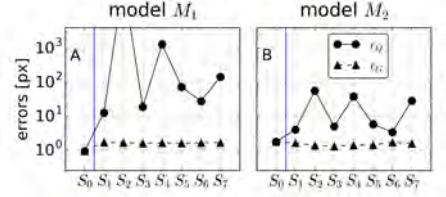
Sets of points



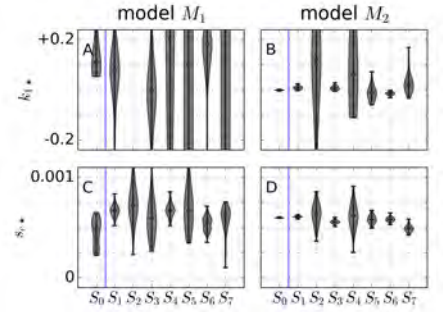
Errors  $\epsilon_P$



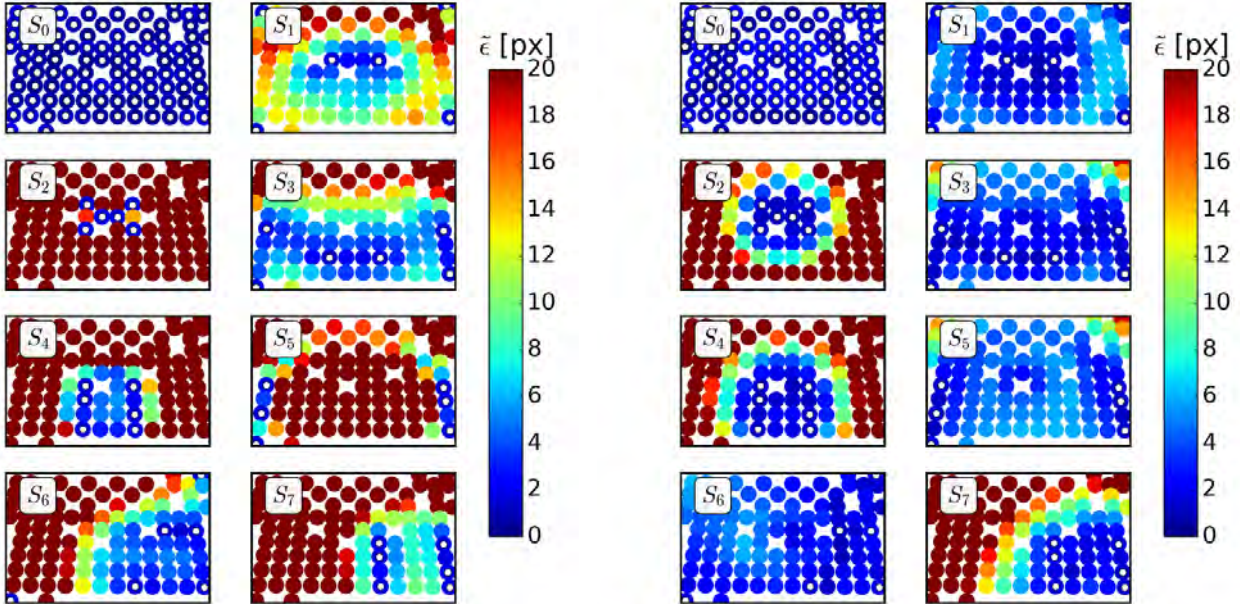
Errors  $\epsilon_Q$  and  $\epsilon_G$



Intrinsic:  $k_{1*}$  and  $s_{c*}$

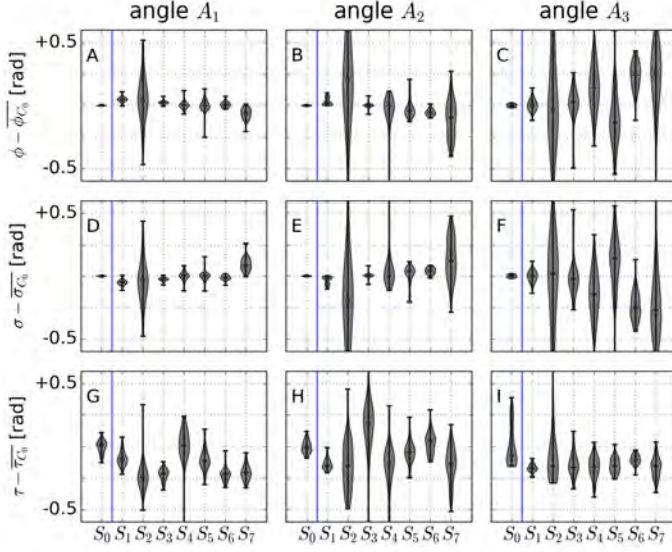


Errors  $\tilde{\epsilon}$  for model  $M_1$  (left panels) and model  $M_2$  (right panels)

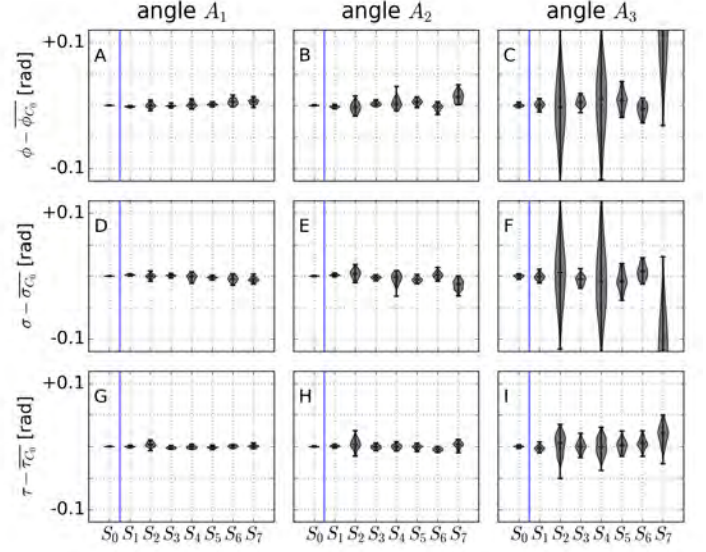


## Camera 2, 6 GCPs ( $A_1, A_2$ and $A_3$ )

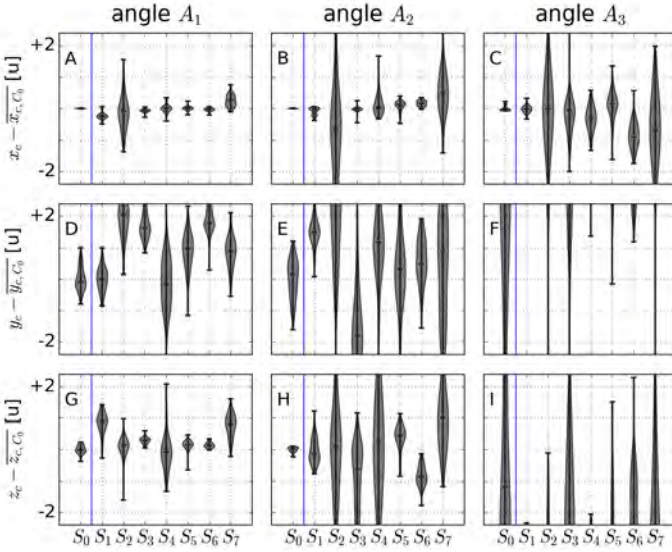
Extrinsic: eulerian angles for  $M_1$



Extrinsic: eulerian angles for  $M_2$



Extrinsic: camera position for  $M_1$



Extrinsic: camera position for  $M_2$

