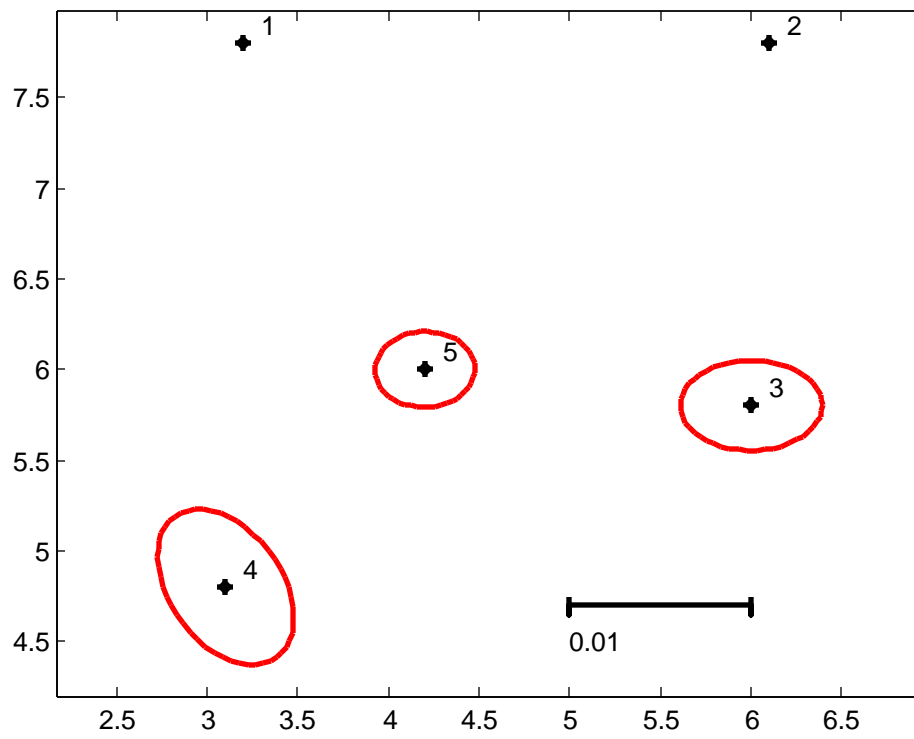


50 pct conf ellipse terrestrial block with control points



photo\_gcp.lst

hw2b\_sol

linear intersection results

XYZ =  
3. 1576      7. 7045      0. 37989  
6. 2034      7. 9431      0. 40863  
6. 2816      6. 0239      3. 5941  
3. 1399      4. 8571      3. 7917  
4. 2539      6. 0626      1. 5752

nobs =

15

iter =

1

parameter values

XL =  
0. 4      2. 3      4. 5

YL =  
3. 9      0. 6      2. 4

ZL =  
1. 5      1. 6      1. 5

omega =  
1. 4773      1. 5139      1. 6057

phi =  
-0. 97536      -0. 40084      0

kappa =  
-0. 077436      -0. 022212      0

XYZ =

3. 1576      7. 7045      0. 37989  
6. 2034      7. 9431      0. 40863  
6. 2816      6. 0239      3. 5941  
3. 1399      4. 8571      3. 7917  
4. 2539      6. 0626      1. 5752

matrices

B =

Columns 1 through 6

-6. 0712	-39. 635	6. 9557	6. 724	-4. 9174	-0. 14803
30. 695	-5. 3175	-12. 633	1. 6294	1. 099	7. 7444
-4. 4187	-34. 907	3. 5383	2. 81	-4. 0345	-0. 0038545
20. 204	-2. 7881	-0. 52435	0. 62475	0. 4214	4. 8833
12. 157	-37. 482	-14. 178	2. 0391	-5. 725	0. 079179
15. 178	-6. 7849	8. 9955	-1. 7188	-1. 1593	6. 0032
29. 562	-38. 217	-31. 772	4. 3215	-12. 821	0. 18797
27. 342	-13. 66	9. 6361	-9. 2382	-6. 2313	13. 647
0. 5985	-35. 148	-2. 4341	3. 9103	-6. 9696	0. 034359
17. 269	-2. 9207	2. 8849	-0. 11301	-0. 076229	7. 9828

0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0

Columns 7 through 12

0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-1. 3223	-37. 895	4. 337	5. 2145	-0. 6425	-0. 075785
36. 602	-2. 0323	-10. 034	0. 34751	0. 81869	5. 0114
-2. 2138	-35. 249	3. 175	3. 7228	-1. 9759	0. 019085
31. 302	-0. 50806	3. 0397	0. 23449	0. 55242	4. 1732



0	0	0	photo_gcp.lst	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-2.0391	5.725	-0.079179	0	0	0
1.7188	1.1593	-6.0032	0	0	0
0	0	0	-4.3214	12.821	-0.18797
0	0	0	9.2382	6.2312	-13.647
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-4.4967	3.3261	-0.068377	0	0	0
0.65854	1.5514	-5.5347	0	0	0
0	0	0	-8.5218	1.632	0.095775
0	0	0	1.7603	4.1471	-8.7298
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-9.4728	4.565	0.15941	0	0	0
0	5.369	-9.2911	0	0	0
0	0	0	-13.803	-7.3997	-0.2584
0	0	0	0	12.476	-13.376
0	0	0	0	0	0
0	0	0	0	0	0

Columns 31 through 33

0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
-3.9103	6.9696	-0.034359
0.11301	0.076229	-7.9828
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
-5.706	2.0411	0.018379
-0.010129	-0.023862	-6.0569
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
-9.555	-0.64147	-0.022401
0	0.19619	-9.554

f =

1.5852  
1.9673  
0.48965  
1.6337  
0.028466  
1.6851  
-0.0089054  
2.4127  
0.36993  
1.5991  
-1.9909  
-1.03  
-1.4883  
-1.102  
-1.3576  
-0.84509  
-1.8142

0.050897  
-1.6166  
-0.7619  
1.0756  
-0.084917  
1.4916  
-0.38946  
2.8638  
-0.84199  
3.0949  
-1.7827  
1.8839  
-0.67814

C =

Columns 1 through 13

0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0

Columns 14 through 26

0	0	0	0	0	1	0	0	0	0	0	0	0
0	0	0	0	0	0	1	0	0	0	0	0	0
0	0	0	0	0	0	0	1	0	0	0	0	0
0	0	0	0	0	0	0	0	1	0	0	0	0
0	0	0	0	0	0	0	0	0	1	0	0	0
0	0	0	0	0	0	0	0	0	0	1	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0

Columns 27 through 33

0	0	0	0	0	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0
1	0	0	0	0	0	0

g =

0.042369  
0.095514  
0.020111  
-0.10341  
-0.14311  
0.091368  
-0.094108

sol =

0.08387  
-0.026047  
0.069126  
0.12545  
0.090009  
0.020441  
-0.041629  
0.040034  
-0.012042  
-0.063472  
-0.0086293  
0.13512  
0.014621  
-0.030888  
-0.0011864  
0.026738  
0.10753  
-0.088636  
0.042369  
0.095514  
0.020111  
-0.10341  
-0.14311  
0.091368  
-0.28111  
-0.2288  
-0.094108  
-0.02103  
-0.061235  
-0.081666  
-0.044852  
-0.067283





photo\_gcp.lst

Columns 25 through 30

0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-2.0276	6.1573	-0.0067925	0	0	0
1.8776	1.2036	-6.2906	0	0	0
0	0	0	-4.1197	13.301	-0.015839
0	0	0	9.4931	6.0802	-13.482
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-4.8711	3.5752	-0.15294	0	0	0
0.60903	1.5961	-6.0048	0	0	0
0	0	0	-8.5934	1.7445	0.12541
0	0	0	1.5034	3.95	-9.0811
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-10.071	4.3694	0.2287	0	0	0
0.16467	6.2194	-9.9058	0	0	0
0	0	0	-15.146	-8.8931	-0.42316
0	0	0	0.4075	14.479	-14.164
0	0	0	0	0	0
0	0	0	0	0	0

Columns 31 through 33

0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
-4.0106	7.3672	-0.0010282
0.14627	0.096045	-8.3681
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
-5.7287	2.0912	0.0032009
-0.044392	-0.12773	-6.1115
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
0	0	0
-10.085	-0.91665	-0.033496
-0.0098645	0.56451	-10.037

f =

-0.12181  
 0.0062918  
 -0.040116  
 0.064557  
 0.017049  
 0.11974  
 0.004437  
 0.21612  
 -0.030951  
 0.07765  
 -0.031653  
 0.0053338  
 -0.012714  
 0.0030815  
 -0.0070196  
 0.0072801



-0.01046  
0.0017404  
-0.019291  
0.0089158  
-0.014468  
0.0051573  
0.0028644  
0.030614  
-0.075945  
0.16839  
-0.18705  
0.20175  
-0.041371  
0.056843

C =

Columns 1 through 13

0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0

Columns 14 through 26

0	0	0	0	0	1	0	0	0	0	0	0	0
0	0	0	0	0	0	1	0	0	0	0	0	0
0	0	0	0	0	0	0	1	0	0	0	0	0
0	0	0	0	0	0	0	0	1	0	0	0	0
0	0	0	0	0	0	0	0	0	1	0	0	0
0	0	0	0	0	0	0	0	0	0	1	0	0
0	0	0	0	0	0	0	0	0	0	0	0	0

Columns 27 through 33

0	0	0	0	0	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0
0	0	0	0	0	0	0
1	0	0	0	0	0	0

g =

0  
0  
0  
0  
0  
0  
0

sol =

0.0084219  
-0.0022404  
0.0070922  
-0.024304  
0.010891  
-0.017383  
0.0039847  
-0.0041272  
0.00014189  
-0.034905  
0.0085997  
-0.028833  
0.0028549  
-0.0035767  
0.0022741  
-0.023978  
-0.0072674  
-0.011442  
0  
2.6464e-019  
0  
0  
0  
0  
0.0021296  
0.006748  
0  
-0.015824  
0.0048591  
-0.0084616  
-0.0083684

```
0.0046953
-0.0075189
8.8261e-008
-2.4771e-008
2.3013e-008
-5.9181e-008
4.1021e-008
-3.6068e-008
1.0146e-008
corrections
ans =
0.026322      0.016302      0.01598
iter =
3
corrections
ans =
9.7075e-005    0.0002258    0.00011299
iter =
4
corrections
ans =
2.1125e-007    6.1557e-008    4.1647e-008
iter =
5
corrections
ans =
1.4859e-010    2.1145e-010    2.0451e-010
iter =
6
corrections
ans =
4.7807e-011    7.9609e-011    3.0322e-011
test =
2.7355
cv1 =
0.48442
cv2 =
11.143
v =
0.00052567
7.0299e-005
-0.00030612
0.002723
-0.00066946
-0.0029516
-0.00040432
0.0011455
0.00082659
-0.0013805
-0.0017588
-0.0018469
0.00041784
-0.001218
0.0018746
0.0024171
0.00097771
-0.0023938
-0.0020534
0.0034274
0.00079137
0.0011863
-0.00032469
-0.0013461
-0.001172
0.00035338
4.333e-005
0.00046042
0.00080208
-0.00094664
diary off
```

```
% hw2b_sol.m 15-feb-09
% 3-photo bundle block adj.
% approx as given in the problem
% adjust the linear intersection to divide by
% Y-YL instead of Z-ZL since the latter was near
% zero for at least one point
```

```
x0=0;
y0=0;
foc=35;
```

```
degrad=180/pi;
omega=zeros(1,3);
phi=zeros(1,3);
kappa=zeros(1,3);
% initial approximations
```

```
thz=-56/degrad;
thx=87/degrad;
m=m1(thx)*m3(thz);
p=asin(m(3,1));
w=atan2(-m(3,2)/cos(p),m(3,3)/cos(p));
k=atan2(-m(2,1)/cos(p),m(1,1)/cos(p));
omega(1)=w;
phi(1)=p;
kappa(1)=k;
```

```
thz=-23/degrad;
thx=87/degrad;
m=m1(thx)*m3(thz);
p=asin(m(3,1));
w=atan2(-m(3,2)/cos(p),m(3,3)/cos(p));
k=atan2(-m(2,1)/cos(p),m(1,1)/cos(p));
omega(2)=w;
phi(2)=p;
kappa(2)=k;
```

```
thz=0/degrad;
thx=92/degrad;
m=m1(thx)*m3(thz);
p=asin(m(3,1));
w=atan2(-m(3,2)/cos(p),m(3,3)/cos(p));
k=atan2(-m(2,1)/cos(p),m(1,1)/cos(p));
omega(3)=w;
phi(3)=p;
kappa(3)=k;
```

```
XL=[0.4 2.3 4.5];
YL=[3.9 0.6 2.4];
ZL=[1.5 1.6 1.5];
```

```
% temp
%plot(XL, YL, 'b+');
%hold on
```

```
% ok now intersect for the object space coordinates
```

```
obs=[ 1 1 -14.218 -8.923;
      1 2 -1.014 -5.172;
      1 3 8.967 12.493;
      1 4 9.645 29.359;
      1 5 2.515 0.835;
      2 1 -8.043 -3.307;
      2 2 4.528 -2.073;
      2 3 9.765 13.540;
      2 4 -5.737 20.399;
      2 5 -0.415 2.446;
      3 1 -10.004 -8.592;
      3 2 9.345 -7.780;
      3 3 14.013 19.469;
      3 4 -21.869 32.213;
      3 5 -4.235 0.175];
```

```
XYZ=zeros(5,3);
B=zeros(6,3);
f=zeros(6,1);
```

```

% use linear algorithm and pseudo LS
for i=1:5
    for j=1:3
        dx=i+(j-1)*5;
        x=obs(dx,3);
        y=obs(dx,4);
        iv=[x-x0; y-y0; -foc];
        m=m3(kappa(j))*m2(phi(j))*m1(omega(j));
        %i f(i==1)
        % disp('rot matrix');
        % j
        % m
        % end
        %m
        uvw=m'*iv;
        %uvw0=m'*[0;0;-foc];

        % temp
        %i p=[uvw(1);uvw(2)];
        %l ip=sqrt(ip(1)^2 + ip(2)^2);
        %i p=(ip/lip)*2;
        %i p(1)=ip(1) + XL(j);
        %i p(2)=ip(2) + YL(j);
        %i f(i==5)
        % plot(ip(1),ip(2),'r');
        % end
        %i p=[uvw0(1);uvw0(2)];
        %l ip=sqrt(ip(1)^2 + ip(2)^2);
        %i p=(ip/lip)*2;
        %i p(1)=ip(1) + XL(j);
        %i p(2)=ip(2) + YL(j);
        %i f(i==5)
        % plot(ip(1),ip(2),'r');
        % end
        %i f(i==1)
        % uvw
        % end
        c1=uvw(1)/uvw(2);
        c2=uvw(3)/uvw(2);
        row=(j-1)*2+1;
        B(row,:)= [1 -c1 0];
        B(row+1,:)= [0 -c2 1];
        f(row)= XL(j)-c1*YL(j);
        f(row+1)=ZL(j)-c2*YL(j);
        end
        %i f(i==1)
        % B
        % f
        % end
        sol=inv(B'*B)*B'*f;
        %disp('linear intersection');
        %cond(B'*B)
        XYZ(i,:)= [sol(1) sol(2) sol(3)];
        end
    disp('linear intersection results');
    XYZ

    % temp
    %plot(XYZ(:,1),XYZ(:,2),'g*');
    %axis equal

% ok now we have all approximations - do the bundle block

% sigma0 squared is (0.005)^2
% then W=I
nobs=15
for iter=1:6
    B=zeros(30,33);
    iter
    for i=1:nobs
        row=(i-1)*2 + 1;
        phn=obs(i,1);
        ptn=obs(i,2);
        x=obs(i,3);
        y=obs(i,4);
        w=omega(phn);
        p=phi(phn);
        k=kappa(phn);
        X=XYZ(ptn,1);

```

hw2b\_sol . m

```
Y=XYZ(ptn, 2);
Z=XYZ(ptn, 3);
res=lincol(x, y, w, p, k, XL(phn), YL(phn), ZL(phn), X, Y, Z, x0, y0, foc);
colpho=(phn-1)*6 + 1;
colpnt=18 + (ptn-1)*3 + 1;
B(row: row+1, colpho: colpho+5)=res(1: 2, 2: 7);
B(row: row+1, colpnt: colpnt+2)=res(1: 2, 8: 10);
f(row: row+1)=-res(1: 2, 1);
end
N=B'*B;
t=B'*f;
C=zeros(7, 33);
g=zeros(7, 1);
C(1, 19)=1;
C(2, 20)=1;
C(3, 21)=1;
C(4, 22)=1;
C(5, 23)=1;
C(6, 24)=1;
C(7, 27)=1;
g(1)=- (XYZ(1, 1)-3. 2);
g(2)=- (XYZ(1, 2)-7. 8);
g(3)=- (XYZ(1, 3)-0. 4);
g(4)=- (XYZ(2, 1)-6. 1);
g(5)=- (XYZ(2, 2)-7. 8);
g(6)=- (XYZ(2, 3)-0. 5);
g(7)=- (XYZ(3, 3)-3. 5);
zer77=zeros(7, 7);
NE=[-N C'; C zer77];
NEv=[-t; g];
%keyboard
M=inv(NE);
sol=inv(NE)*NEv;
del=sol(1:33); % this is the delta vector
if(iter <= 2)
    disp('parameter values');
    XL
    YL
    ZL
    omega
    phi
    kappa
    XYZ
    disp('matrices');
    B
    f
    C
    g
    sol
end

avgx=abs(sol(19))+abs(sol(22))+abs(sol(25))+abs(sol(28))+abs(sol(31));
avgy=abs(sol(20))+abs(sol(23))+abs(sol(26))+abs(sol(29))+abs(sol(32));
avgz=abs(sol(21))+abs(sol(24))+abs(sol(27))+abs(sol(30))+abs(sol(33));
disp('corrections');
[avgx avgy avgz]
omega=omega + [sol(1) sol(7) sol(13)];
phi =phi + [sol(2) sol(8) sol(14)];
kappa=kappa + [sol(3) sol(9) sol(15)];
XL=XL + [sol(4) sol(10) sol(16)];
YL=YL + [sol(5) sol(11) sol(17)];
ZL=ZL + [sol(6) sol(12) sol(18)];
XYZ(1,:)=XYZ(1,:) + [sol(19) sol(20) sol(21)];
XYZ(2,:)=XYZ(2,:) + [sol(22) sol(23) sol(24)];
XYZ(3,:)=XYZ(3,:) + [sol(25) sol(26) sol(27)];
XYZ(4,:)=XYZ(4,:) + [sol(28) sol(29) sol(30)];
XYZ(5,:)=XYZ(5,:) + [sol(31) sol(32) sol(33)];
% parameter order
% w p k XL YL ZL w p k XL YL ZL w p k XL YL ZL x y z x y z x y z x y z x y z
% 1 2 3 4 5 6 7 8 9 10 11 12 13 14 15 16 17 18 19 20 21 22 23 24 25 26 27 28 29 30 31 32 33
% with 7 constraints, full normals are 40 x 40
end

% error prop
al pha=M(1: 33, 1: 33);
Qdd=-al pha;
v=f - B*del;
nphopnt=15;
vx=[v(1); v(3); v(5); v(7); v(9); v(11); v(13); v(15); v(17); v(19); v(21); v(23); v(25); v(27); v(29)];
```

```

hw2b_sol.m
vy=[v(2);v(4);v(6);v(8);v(10);v(12);v(14);v(16);v(18);v(20);v(22);v(24);v(26);v(28);v(30)];
rmsx=vx'*vx/nphopnt;
rmsy=vy'*vy/nphopnt;
W=eye(30);
Q=eye(30);
Qvv=Q - B*Qdd*B';
trQvv=trace(Qvv);
% ok this last statement confirms that r=4
r=4;
si gma0_sqr=0.005^2;
test=v'*v/si gma0_sqr;
P1=.025;
P2=.975;
cv1=chi2i nv(P1, r);
cv2=chi2i nv(P2, r);
test
cv1
cv2

% ok pass, scale Qdd by prior si gma0_sqr

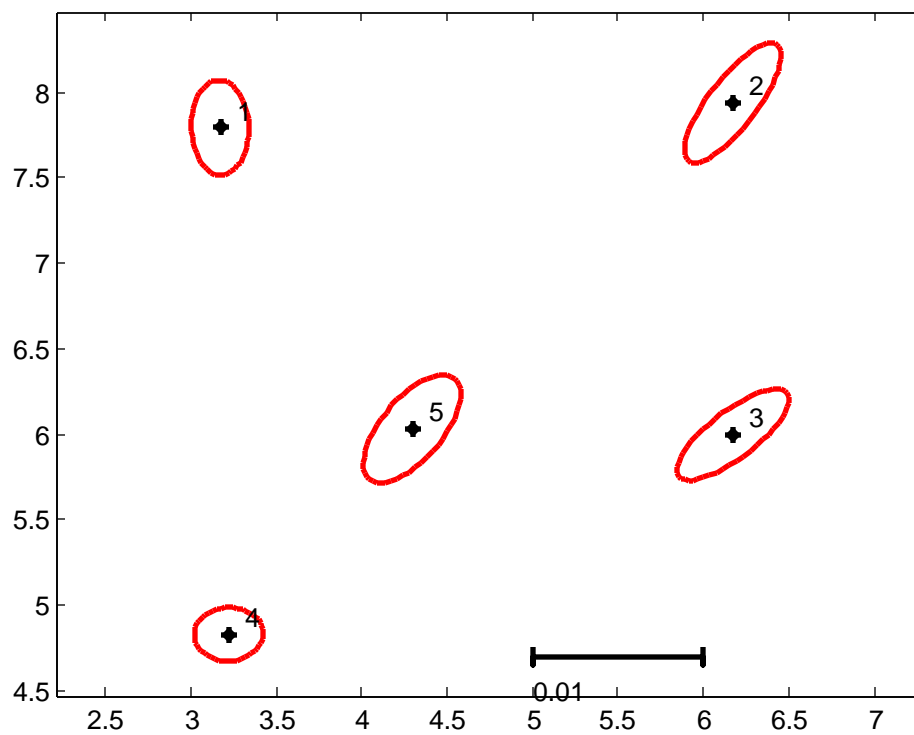
Sdd=si gma0_sqr*Qdd;
for i=1:5
    idx=19 + (i-1)*3;
    cov=Sdd(idx:idx+1, idx:idx+1);
    glob=1; % pass
    prob=0.5;
    factr=100;
    plot_conf_ell(cov, glob, r, prob, XYZ(i, 1), XYZ(i, 2), factr);
    plot(XYZ(i, 1), XYZ(i, 2), 'k*', 'linewidth', 2);
    hold on
    nudge=0.1;
    text(XYZ(i, 1)+nudge, XYZ(i, 2)+nudge, num2str(i));
end

sb0x=5;
sb0y=4.7;
sb1x=sb0x + 1;
y1=sb0y-0.05;
y2=sb0y;
y3=sb0y+0.05;
x=[sb0x sb0x sb0x sb1x sb1x sb1x];
y=[y3 y1 y2 y2 y1 y3];
plot(x, y, 'k-', 'linewidth', 2);
text(5, 4.5, '0.01');

title('50 pct conf ellipse terrestrial block with control points');
axis equal
zoomout;
v

```

50 pct conf ellipse terrestrial block with inner constraints



photo\_i.c.lst

hw2b\_solic

B =

1	-0.66425	0
0	0.34574	1
1	-0.17594	0
0	0.14604	1
1	0.28357	0
0	0.20878	1

f =

- 2.1906
- 2.8484
- 2.1944
- 1.6876
- 5.1806
- 2.0011

Linear intersection results

XYZ =

3.1576	7.7045	0.37989
6.2034	7.9431	0.40863
6.2816	6.0239	3.5941
3.1399	4.8571	3.7917
4.2539	6.0626	1.5752

nobs =

15

iter =

1

B =

Columns 1 through 6

-6.0712	-39.635	6.9557	6.724	-4.9174	-0.14803
30.695	-5.3175	-12.633	1.6294	1.099	7.7444
-4.4187	-34.907	3.5383	2.81	-4.0345	-0.0038545
20.204	-2.7881	-0.52435	0.62475	0.4214	4.8833
12.157	-37.482	-14.178	2.0391	-5.725	0.079179
15.178	-6.7849	8.9955	-1.7188	-1.1593	6.0032
29.562	-38.217	-31.772	4.3215	-12.821	0.18797
27.342	-13.66	9.6361	-9.2382	-6.2313	13.647
0.5985	-35.148	-2.4341	3.9103	-6.9696	0.034359
17.269	-2.9207	2.8849	-0.11301	-0.076229	7.9828
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0

Columns 7 through 12

0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-1.3223	-37.895	4.337	5.2145	-0.6425	-0.075785
36.602	-2.0323	-10.034	0.34751	0.81869	5.0114
-2.2138	-35.249	3.175	3.7228	-1.9759	0.019085
31.302	-0.50806	3.0397	0.23449	0.55242	4.1732
7.0035	-37.078	-12.695	4.4968	-3.3261	0.068377
33.113	-3.9283	8.4074	-0.65854	-1.5514	5.5347
3.1691	-36.522	-20.45	8.5219	-1.632	-0.095775
46.253	3.3682	-7.5512	-1.7603	-4.1471	8.7298
-0.15099	-35.107	-1.6841	5.706	-2.0411	-0.018379
33.087	-0.68141	-2.0316	0.010129	0.023862	6.0569





			photo_i.c.lst		
0	0	0	-4.3214	12.821	-0.18797
0	0	0	9.2382	6.2312	-13.647
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-4.4967	3.3261	-0.068377	0	0	0
0.65854	1.5514	-5.5347	0	0	0
0	0	0	-8.5218	1.632	0.095775
0	0	0	1.7603	4.1471	-8.7298
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
0	0	0	0	0	0
-9.4728	4.565	0.15941	0	0	0
0	5.369	-9.2911	0	0	0
0	0	0	-13.803	-7.3997	-0.2584
0	0	0	0	12.476	-13.376
0	0	0	0	0	0
0	0	0	0	0	0
Columns 31 through 33					
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
-3.9103	6.9696	-0.034359			
0.11301	0.076229	-7.9828			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
-5.706	2.0411	0.018379			
-0.010129	-0.023862	-6.0569			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
0	0	0			
-9.555	-0.64147	-0.022401			
0	0.19619	-9.554			

f =

1.5852
1.9673
0.48965
1.6337
0.028466
1.6851
-0.0089054
2.4127
0.36993
1.5991
-1.9909
-1.03
-1.4883
-1.102
-1.3576
-0.84509
-1.8142
0.050897
-1.6166
-0.7619
1.0756
-0.084917
1.4916

```
-0.38946
 2.8638
-0.84199
 3.0949
 -1.7827
  1.8839
-0.67814
corrections
ans =  0.29011      0.18353      0.20642
iter =
 2
corrections
ans =  0.015069    0.013022    0.013574
iter =
 3
corrections
ans =  4.5149e-005  3.049e-005  3.9339e-005
iter =
 4
corrections
ans =  3.7692e-009  9.2136e-009  5.4528e-009
we converged
rmsx =  0.0010447
rmsy =  0.0018622
test =  2.7355
cv1 =  0.48442
cv2 =  11.143
v =  0.00052566
    7.0296e-005
   -0.00030611
    0.002723
   -0.00066947
   -0.0029516
  -0.00040432
    0.0011455
    0.00082659
   -0.0013805
   -0.0017588
   -0.0018469
    0.00041784
   -0.001218
    0.0018746
    0.0024171
    0.00097771
   -0.0023938
   -0.0020534
    0.0034274
    0.00079137
    0.0011863
  -0.00032469
   -0.0013461
   -0.001172
    0.00035339
    4.3331e-005
    0.00046042
    0.00080208
   -0.00094664
di ary off
```

```

% hw2b_sol i c. m 15-feb-09
% 3-photo bundle block adj.
% approx as given in the problem
% adjust the linear intersection to divide by
% Y-YL instead of Z-ZL since the latter was near
% zero for at least one point
% for this version use inner constraints with the object points

```

```

x0=0;
y0=0;
foc=35;

```

```

degrad=180/pi;
omega=zeros(1,3);
phi=zeros(1,3);
kappa=zeros(1,3);
% initial approximations

```

```

thz=-56/degrad;
thx=87/degrad;
m=m1(thx)*m3(thz);
p=asin(m(3,1));
w=atan2(-m(3,2)/cos(p),m(3,3)/cos(p));
k=atan2(-m(2,1)/cos(p),m(1,1)/cos(p));
omega(1)=w;
phi(1)=p;
kappa(1)=k;

```

```

thz=-23/degrad;
thx=87/degrad;
m=m1(thx)*m3(thz);
p=asin(m(3,1));
w=atan2(-m(3,2)/cos(p),m(3,3)/cos(p));
k=atan2(-m(2,1)/cos(p),m(1,1)/cos(p));
omega(2)=w;
phi(2)=p;
kappa(2)=k;

```

```

thz=0/degrad;
thx=92/degrad;
m=m1(thx)*m3(thz);
p=asin(m(3,1));
w=atan2(-m(3,2)/cos(p),m(3,3)/cos(p));
k=atan2(-m(2,1)/cos(p),m(1,1)/cos(p));
omega(3)=w;
phi(3)=p;
kappa(3)=k;

```

```

XL=[0.4 2.3 4.5];
YL=[3.9 0.6 2.4];
ZL=[1.5 1.6 1.5];

```

```

% temp
%plot(XL, YL, 'b+');
%hold on

```

```

% ok now intersect for the object space coordinates

```

```

obs=[ 1 1 -14.218 -8.923;
      1 2 -1.014 -5.172;
      1 3 8.967 12.493;
      1 4 9.645 29.359;
      1 5 2.515 0.835;
      2 1 -8.043 -3.307;
      2 2 4.528 -2.073;
      2 3 9.765 13.540;
      2 4 -5.737 20.399;
      2 5 -0.415 2.446;
      3 1 -10.004 -8.592;
      3 2 9.345 -7.780;
      3 3 14.013 19.469;
      3 4 -21.869 32.213;
      3 5 -4.235 0.175];

```

```

XYZ=zeros(5,3);
B=zeros(6,3);

```

```

f=zeros(6,1);
% use linear algorithm and pseudo LS
for i=1:5
    for j=1:3
        idx=i+(j-1)*5;
        x=obs(idx,3);
        y=obs(idx,4);
        iv=[x-x0; y-y0; -foc];
        m=m3(kappa(j))*m2(phi(j))*m1(omega(j));
        uvw=m'*iv;
        c1=uvw(1)/uvw(2);
        c2=uvw(3)/uvw(2);
        row=(j-1)*2+1;
        B(row,:)= [1 -c1 0];
        B(row+1,:)= [0 -c2 1];
        f(row)= XL(j)-c1*YL(j);
        f(row+1)=ZL(j)-c2*YL(j);
    end
    if(i==1)
        B
        f
    end
    sol=inv(B'*B)*B'*f;
    XYZ(i,:)=[sol(1) sol(2) sol(3)];
end
disp('Linear intersection results');
XYZ

% temp
%plot(XYZ(:,1),XYZ(:,2),'g*');
%axis equal

% ok now we have all approximations - do the bundle block

% sigma0 squared is (0.005)^2
% then W=I
nobs=15;
W=eye(30);
Q=eye(30);
prior_qf=1.0e06;
keep_going=1;
iter=0;
while(keep_going == 1)
    iter=iter+1;
    B=zeros(30,33);
    for i=1:nobs
        row=(i-1)*2+1;
        phn=obs(i,1);
        ptn=obs(i,2);
        x=obs(i,3);
        y=obs(i,4);
        w=omega(phn);
        p=phi(phn);
        k=kappa(phn);
        X=XYZ(ptn,1);
        Y=XYZ(ptn,2);
        Z=XYZ(ptn,3);
        res=lincol(x,y,w,p,k,XL(phn),YL(phn),ZL(phn),X,Y,Z,x0,y0,foc);
        %phn
        %ptn
        %x
        %y
        %w
        %p
        %k
        %XL(phn)
        %YL(phn)
        %ZL(phn)
        %X
        %Y
        %Z
        %res(1)
        %pause
        colpho=(phn-1)*6+1;
        colpnt=18+(ptn-1)*3+1;
        B(row:row+1,colpho:colpho+5)=res(1:2,2:7);
        B(row:row+1,colpnt:colpnt+2)=res(1:2,8:10);
        f(row:row+1)=-res(1:2,1);
    end
end

```

```

if( iter == 1)
    B
    f
    end
N=B'*B;
t=B'*f;
C=zeros(7,33);
g=zeros(7,1);
for i=1:5
    idx=18 + (i-1)*3 + 1;
    X=XYZ(i,1);
    Y=XYZ(i,2);
    Z=XYZ(i,3);
    C(:,idx:idx+2)=[ 1 0 0;
        0 1 0;
        0 0 1;
        0 Z -Y;
        -Z 0 X;
        Y -X 0;
        X Y Z];
    end
g=zeros(7,1);

zer77=zeros(7,7);
NE=[-N C'; C zer77];
NEv=[-t; g];
%keyboard
M=inv(NE);
sol=inv(NE)*NEv;
del=sol(1:33); % this is the delta vector
avgx=abs(sol(19))+abs(sol(22))+abs(sol(25))+abs(sol(28))+abs(sol(31));
avgy=abs(sol(20))+abs(sol(23))+abs(sol(26))+abs(sol(29))+abs(sol(32));
avgz=abs(sol(21))+abs(sol(24))+abs(sol(27))+abs(sol(30))+abs(sol(33));
disp(' corrections');
[avgx avgy avgz]
omega=omega + [sol(1) sol(7) sol(13)];
phi =phi + [sol(2) sol(8) sol(14)];
kappa=kappa + [sol(3) sol(9) sol(15)];
XL=XL + [sol(4) sol(10) sol(16)];
YL=YL + [sol(5) sol(11) sol(17)];
ZL=ZL + [sol(6) sol(12) sol(18)];
XYZ(1,:)=XYZ(1,:) + [sol(19) sol(20) sol(21)];
XYZ(2,:)=XYZ(2,:) + [sol(22) sol(23) sol(24)];
XYZ(3,:)=XYZ(3,:) + [sol(25) sol(26) sol(27)];
XYZ(4,:)=XYZ(4,:) + [sol(28) sol(29) sol(30)];
XYZ(5,:)=XYZ(5,:) + [sol(31) sol(32) sol(33)];
% parameter order
% w p k XL YL ZL w p k XL YL ZL w p k XL YL ZL x y z x y z x y z x y z x y z
% 1 2 3 4 5 6 7 8 9 10 11 12 13 14 15 16 17 18 19 20 21 22 23 24 25 26 27 28 29 30 31 32 33
% with 7 constraints, full normals are 40 x 40
% check convergence
v=f - B*del;
qf=v'*W*v;
if(abs(qf - prior_qf)/qf < 0.00001)
    keep_going=0;
    disp('we converged');
    end
if( iter > 10)
    keep_going=0;
    disp('no convergence');
    end
prior_qf=qf;
end

% error prop
alpha=M(1:33,1:33);
Qdd=-alpha;
v=f - B*del;
nphopnt=15;
vx=[v(1); v(3); v(5); v(7); v(9); v(11); v(13); v(15); v(17); v(19); v(21); v(23); v(25); v(27); v(29)];
vy=[v(2); v(4); v(6); v(8); v(10); v(12); v(14); v(16); v(18); v(20); v(22); v(24); v(26); v(28); v(30)];
rmsx=sqrt(vx'*vx/nphopnt)
rmsy=sqrt(vy'*vy/nphopnt)
Qvv=Q - B*Qdd*B';
trQvv=trace(Qvv);
% ok this last statement confirms that r=4
r=4;
sigma0_sqr=0.005^2;
test=v'*v/sigma0_sqr;

```

```

P1=.025;
P2=.975;
cv1=chi2inv(P1,r);
cv2=chi2inv(P2,r);
test
cv1
cv2

% ok pass, scale Qdd by prior sigma0_sqr

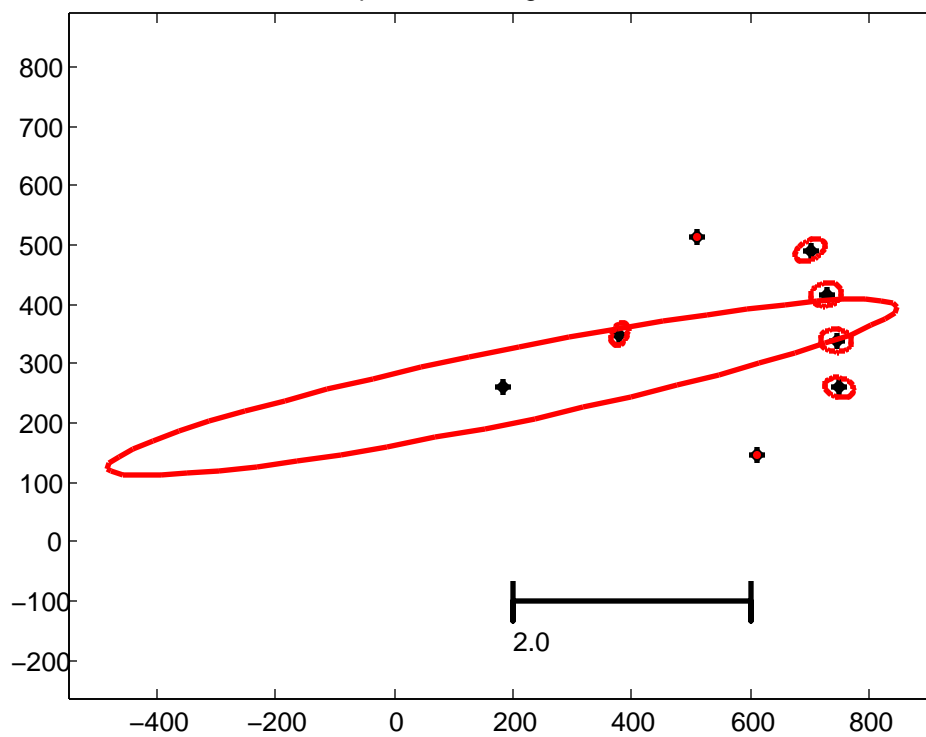
Sdd=sigma0_sqr*Qdd;
for i=1:5
    idx=19+(i-1)*3;
    cov=Sdd(idx:idx+1,idx:idx+1);
    glob=1; % pass
    prob=0.5;
    factr=300;
    plot_conf_ell(cov,glob,r,prob,XYZ(i,1),XYZ(i,2),factr);
    plot(XYZ(i,1),XYZ(i,2),'k-','linewidth',2);
    hold on
    nudge=0.1;
    text(XYZ(i,1)+nudge,XYZ(i,2)+nudge,num2str(i));
end

sb0x=5;
sb0y=4.7;
sb1x=sb0x+1;
y1=sb0y-0.05;
y2=sb0y;
y3=sb0y+0.05;
x=[sb0x sb0x sb0x sb1x sb1x sb1x];
y=[y3 y1 y2 y2 y1 y3];
plot(x,y,'k-','linewidth',2);
text(5.45,'0.01');

title('50 pct conf ellipse terrestrial block with inner constraints');
axis equal
zoomout;
v

```

2D network plot with enlarged error scale shown





```
net2d_ap_final
iter =
  1
iter =
  2
iter =
  3
convergence OK
V =
  2.3378e-005
 -0.00012332
 -0.00016911
 -0.00011501
 -1.7663e-005
 -0.00011854
 -0.00033107
  0.00039221
 -3.7008e-005
  9.7852e-005
 -3.4269e-005
  0.00010475
  0.00039252
 -0.00033758
  0.00010558
vdms =
  0
  0
  4.8221
vdms =
  0
  0
 -25.437
vdms =
  0
  0
 -34.881
vdms =
  0
  0
 -23.722
vdms =
  0
  0
 -3.6433
vdms =
  0
  0
 -24.45
vdms =
  0
 -1
 -8.2875
vdms =
  0
  1
 20.899
vdms =
  0
  0
 -7.6335
vdms =
  0
  0
 20.183
vdms =
  0
  0
 -7.0685
vdms =
  0
  0
 21.606
vdms =
  0
  1
 20.963
vdms =
  0
 -1
```

vdms = -9.631  
0  
0  
21.778  
final coordinates and radius  
P =

510  
515  
380.04  
350.17  
610  
145  
750.05  
259.99  
744.54  
339.32  
728.01  
417.13  
700.79  
491.86  
181.5  
260.37  
568.55

post adj statistics - 2-sided F-test alpha 0.05

test\_stat = 7.5358

cv1 = 1.2373

cv2 = 14.449

we pass

Sdd =

Columns 1 through 6

4.3082e-019	4.4437e-019	2.7126e-019	1.0766e-018	0	0
0	0	0	0	0	0
-7.0473e-019	1.8702e-018	0.0034942	0.0015893	0	0
-3.0358e-018	1.9651e-019	0.0015893	0.0064773	0	0
-5.9469e-019	-5.618e-019	6.4152e-021	-5.0082e-019	0	0
0	0	0	0	0	0
-4.3368e-019	1.6263e-018	1.703e-005	-4.5711e-005	0	0
3.2526e-019	-4.3368e-019	-8.1998e-005	-2.1497e-005	0	0
0	1.9516e-018	0.00018933	8.887e-006	0	0
2.1684e-019	-2.6021e-018	0.00034964	0.00019748	0	0
1.7347e-018	3.2526e-018	9.1659e-005	-4.6385e-006	0	0
0	-3.0358e-018	0.00068041	0.00026211	0	0
0	1.301e-018	-0.00021733	-1.8959e-005	0	0
4.3368e-019	1.7347e-018	0.00081964	0.00016144	0	0
-8.5001e-017	-5.1174e-017	0.0089478	0.0024917	0	0
1.2143e-017	5.6379e-018	0.0021906	0.00076012	0	0

Columns 7 through 12

-4.5729e-019	-3.7198e-019	-2.7194e-019	-7.9852e-019	-5.9653e-019	-8.2399e-019
0	0	0	0	0	0
1.703e-005	-8.1998e-005	0.00018933	0.00034964	9.1659e-005	0.00068041
-4.5711e-005	-2.1497e-005	8.887e-006	0.00019748	-4.6385e-006	0.00026211
-8.431e-018	7.5515e-019	-9.2721e-018	1.2122e-018	-1.3483e-017	-1.8857e-018
0	0	0	0	0	0
0.01109	-0.001565	0.0098588	0.0001659	0.0079213	0.0017174
-0.001565	0.0051969	-0.0029362	0.004053	-0.0030967	0.002408
0.0098588	-0.0029362	0.012893	-0.00054816	0.012046	0.0020431
0.0001659	0.004053	-0.00054816	0.0067237	-0.00092337	0.0049024
0.0079213	-0.0030967	0.012046	-0.00092337	0.012728	0.0011826
0.0017174	0.002408	0.0020431	0.0049024	0.0011826	0.0068449
0.0052537	-0.0020139	0.0072264	-0.00093323	0.0093304	0.00071092
0.0030228	0.00090186	0.0039836	0.0030309	0.0040886	0.0049614
0.021414	-0.040565	0.16997	0.0076599	0.15552	0.033173
-0.0078615	-0.0083818	0.032092	0.002163	0.038588	0.0093855

Columns 13 through 16

-5.7548e-019	-1.0948e-018	7.649e-018	1.5292e-018
0	0	0	0
-0.00021733	0.00081964	0.0089478	0.0021906
-1.8959e-005	0.00016144	0.0024917	0.00076012
-5.844e-018	-2.4345e-018	-1.1393e-016	-2.8582e-017
0	0	0	0
0.0052537	0.0030228	0.021414	-0.0078615
-0.0020139	0.00090186	-0.040565	-0.0083818
0.0072264	0.0039836	0.16997	0.032092
-0.00093323	0.0030309	0.0076599	0.002163
0.0093304	0.0040886	0.15552	0.038588

0.00071092	0.0049614	0.033173	net2d_ap_final.lst.lst
0.011202	0.003424	-0.020436	0.0093855
0.003424	0.0065641	0.019713	0.011279
-0.020436	0.019713	7.9643	0.010999
0.011279	0.010999	1.6133	1.6133
			0.39824

di ary off

net2d\_ap\_final.m

```
% net2d_ap_final.m 28-mar-09
% use added parameters for some of the constraints
% to solve hw2 #2
% first solve with conventional constraints and no a.p.'s
% under this scenario we have B: (15 x 14+3)=(15 x 17), C: (4+4 x 14+3)=(8 x 17)
% N: (17 x 17), Z: (8 x 8)
% taken from the program below - allow for general constraints for testing
% solve by [ -N CT ] [Del] = [-t]
% [ C 0 ] [kc] [g]
% allow for fixed points, inner constraints, etc. with general plotting
% strategy
%1 1 7 6 17 15 31.0
%2 1 6 5 12 39 57.7
%3 1 5 4 9 54 20.6
%4 1 4 3 28 9 7.8
%5 1 3 2 53 22 45.6
%6 2 1 7 27 55 11.1
%7 2 7 6 12 57 33.2
%8 2 6 5 12 34 31.2
%9 2 5 4 11 59 37.7
%10 2 4 3 28 2 12.6
%11 3 2 1 33 8 18.6
%12 3 1 7 29 47 11.1
%13 3 7 6 8 45 12.8
%14 3 6 5 11 16 22.8
%15 3 5 4 15 54 25.9

% (hw4_sol.m 3-nov-08)
% (solve braced quad for hw4)

X=[510; 380; 610; 750; 744. 453; 727. 919; 700. 721; 180];
Y=[515; 350; 145; 260; 339. 329; 417. 113; 491. 840; 260];
R=570;
P=[X(1); Y(1); X(2); Y(2); X(3); Y(3); X(4); Y(4); X(5); Y(5); X(6); Y(6); X(7); Y(7); X(8); Y(8); R];
% 17 x 1 parameter vector X(8), Y(8), R are center and radius of circle

degrad=180/pi;

% obs: seq_num at from to D M S
obs=[1 1 7 6 17 15 31.0;
2 1 6 5 12 39 57.7;
3 1 5 4 9 54 20.6;
4 1 4 3 28 9 7.8;
5 1 3 2 53 22 45.6;
6 2 1 7 27 55 11.1;
7 2 7 6 12 57 33.2;
8 2 6 5 12 34 31.2;
9 2 5 4 11 59 37.7;
10 2 4 3 28 2 12.6;
11 3 2 1 33 8 18.6;
12 3 1 7 29 47 11.1;
13 3 7 6 8 45 12.8;
14 3 6 5 11 16 22.8;
15 3 5 4 15 54 25.9];

n=15;
n0=9;
% 2 angles from endpoints of known baseline to each other point
% except only 1 angle needed to the 4th point on circle
r=6;
c=15;
u=17;
s=8;
% c+s=23, r+u=23 check

si ga=(60/3600)/degrad;
sa2=si ga^2;
si gma0_sqr=1;
w=ones(1, 15);
w=w/sa2;
W=diag(w);

th=zeros(15, 1);
for i=1:15
    D=obs(i, 5);
    M=obs(i, 6);
    S=obs(i, 7);
    th(i)=(D+M/60+S/3600)/degrad;
end
```

```

pi dx=[1 3 5 7 9 11 13 15];
keep_going=1;
iter=0;
while(keep_going == 1)
    iter=iter+1;
    B=zeros(n,u);
    f=zeros(n,1);
    rwi dx=0;

    for i=1:15
        rwi dx=rwi dx+1;
        at=obs(i,2);
        from=obs(i,3);
        to=obs(i,4);
        rs=angle2d(th(i), at, from, to, X, Y);
        B(rwi dx, pi dx(at)) =rs(2);
        B(rwi dx, pi dx(at)+1) =rs(3);
        B(rwi dx, pi dx(from)) =rs(4);
        B(rwi dx, pi dx(from)+1)=rs(5);
        B(rwi dx, pi dx(to)) =rs(6);
        B(rwi dx, pi dx(to)+1) =rs(7);
        f(rwi dx)=-rs(1);
    end

    % ok do not need to eliminate columns as before !!
    % will have singular N

    N=B' *W*B;
    t=B' *W*f;

    % ok now define the constraint equations into C matrix and g
    % first we do conventional (hw4-08) approach

    C=zeros(8,17);
    g=zeros(8,1);
    C(1,1)=1;
    g(1)=- (X(1)-510);
    C(2,2)=1;
    g(2)=- (Y(1)-515);
    C(3,5)=1;
    g(3)=- (X(3)-610);
    C(4,6)=1;
    g(4)=- (Y(3)-145);
    rs=distance2d(R,8,4,X,Y);
    C(5, pi dx(8)) =rs(2);
    C(5, pi dx(8)+1)=rs(3);
    C(5, pi dx(4)) =rs(4);
    C(5, pi dx(4)+1)=rs(5);
    C(5,17)=1;
    g(5)=-rs(1);
    rs=distance2d(R,8,5,X,Y);
    C(6, pi dx(8)) =rs(2);
    C(6, pi dx(8)+1)=rs(3);
    C(6, pi dx(5)) =rs(4);
    C(6, pi dx(5)+1)=rs(5);
    C(6,17)=1;
    g(6)=-rs(1);
    rs=distance2d(R,8,6,X,Y);
    C(7, pi dx(8)) =rs(2);
    C(7, pi dx(8)+1)=rs(3);
    C(7, pi dx(6)) =rs(4);
    C(7, pi dx(6)+1)=rs(5);
    C(7,17)=1;
    g(7)=-rs(1);
    rs=distance2d(R,8,7,X,Y);
    C(8, pi dx(8)) =rs(2);
    C(8, pi dx(8)+1)=rs(3);
    C(8, pi dx(7)) =rs(4);
    C(8, pi dx(7)+1)=rs(5);
    C(8,17)=1;
    g(8)=-rs(1);

    z88=zeros(8,8);
    Mx=[-N C'; C z88];
    vc=[-t; g];

```

```

fulldel=inv(Mx)*vc;
del=fulldel(1:17,1);
%keyboard
P=P+del;

X=[P(1) P(3) P(5) P(7) P(9) P(11) P(13) P(15)];
Y=[P(2) P(4) P(6) P(8) P(10) P(12) P(14) P(16)];
R=P(17);
if(all(abs(del) < 0.00001))
    keepgoing=0;
    disp('convergence OK');
end
if(iter > 10)
    keepgoing=0;
    disp('failed to converge');
end
end

v=F-B*del
for i=1:15
    vdms=raddms(v(i))
end

disp('final coordinates and radius');
P

% ok now post-adjustment statistics

iMx=inv(Mx);
Qdd=-iMx(1:16,1:16);
disp('post adj statistics - 2-sided F-test alpha 0.05');
test_stat=v'*W*v/1.0
cv1=icdf('chi2',0.025,r)
cv2=icdf('chi2',0.975,r)
if((test_stat > cv1) & (test_stat < cv2))
    pass=1;
    disp('we pass');
    Sdd=sigma0_sqr*Qdd
else
    disp('we do not pass');
    pass=0;
    sigma0_sqr_hat=v'*W*v/r;
    Sdd=sigma0_sqr_hat*Qdd
end

% plot the points

plot([X(1) X(2) X(3) X(4) X(5) X(6) X(7) X(8)], [Y(1) Y(2) Y(3) Y(4) Y(5) Y(6) Y(7)
Y(8)], 'k*', 'linewidth', 2);
hold on

% plot the errors

err_factor=200;
for i=1:8
    %disp('plot error, point =');
    %i
    idx=(i-1)*2 + 1;
    cov(1:2,1:2)=Sdd(idx:idx+1, idx:idx+1);
    prob=0.5;
    plot_conf_ell(cov, pass, r, prob, X(i), Y(i), err_factor);
end

% proper aspect ratio
axis equal

% adjust scale
lmt=axis;
xrange=lmt(2)-lmt(1);
yrange=lmt(4)-lmt(3);
x5pct=0.05*xrange;
y5pct=0.05*yrange;
axis([lmt(1)-x5pct lmt(2)+x5pct lmt(3)-y5pct lmt(4)+y5pct]);

% network scale bar
%barx1=lmt(1) + x5pct;
%bary1=lmt(3) + y5pct;
%barx2=barx1 + 100;

```

net2d\_ap\_final.m

```
%bary2=bary1;
%tick=10;
%pxvec=[barx1 barx1 barx1 barx2 barx2 barx2];
%pyvec=[bary1+tick bary1-tick bary2 bary2 bary2-tick bary2+tick];
%plot(pxvec,pyvec,'b-','linewidth',2);
%textx=barx2 + 0.5*x5pct;
%texty=bary2;
%text(textx,texty,'100 m Network');

% error scale bar
%barx1=1mt(1) + x5pct;
%bary1=1mt(3) + 2*y5pct;
%barx2=barx1 + 0.1*err_factor;
%bary2=bary1;
%tick=15;
%pxvec=[barx1 barx1 barx1 barx2 barx2 barx2];
%pyvec=[bary1+tick bary1-tick bary2 bary2 bary2-tick bary2+tick];
%plot(pxvec,pyvec,'r-','linewidth',2);
%textx=barx2 + 0.5*x5pct;
%texty=bary2;
%text(textx,texty,'0.1 m Errors');

%title('Plot of Braced Quad: Network and Errors');

% error scale bar
sb0x=200;
sb0y=-100;
sb1x=sb0x + 2*err_factor;
tick=xrange/40;
y1=sb0y-tick;
y2=sb0y;
y3=sb0y+tick;
x=[sb0x sb0x sb0x sb1x sb1x sb1x];
y=[y3 y1 y2 y2 y1 y3];
plot(x,y,'k-','linewidth',2);
text(sb0x,sb0y-2*tick,'2.0');

title('2D network plot with enlarged error scale shown');
```