# 双目标定结果说明：

注：以下黑色字体为 Matlab 标定工具箱输出的双目标定结果，红色字体为 LenaCV 添加的注释。

Intrinsic parameters of left camera:

Focal Length: fc_left = [ 1451.28636 1453.33641 ] ? [ 6.24190 6.23445 ] //参数含义：[ fc_left_x fc_left_y ] ? [ 误差系数 1 误差系数 2 ]

Principal point: cc_left = [ 580.23189 375.64719 ] ? [ 7.19740 6.52201 ] //参数含义：[ cc_left_x cc_left_y ] ? [ 误差系数 1 误差系数 2 ]

Skew: alpha_c_left = [ 0.00000 ] ? [ 0.00000 ] => angle of pixel axes = 90.00000 ? 0.00000 degrees

Distortion: kc_left = [ 0.03496 0.30850 -0.00023 -0.00484 0.00000 ] ? [ 0.03277 0.41590 0.00191 0.00220 0.00000 ]

//参数含义：[kc_left_01, kc_left_02, kc_left_03, kc_left_04, kc_left_05] ? [误差系数 1 ~ 误差系数 5]

Intrinsic parameters of right camera:

Focal Length: fc_right = [ 1450.99263 1452.75001 ] ? [ 6.20539 6.19683 ] //参数含义：[ fc_ right _x fc_ right _y ] ? [ 误差系数 1 误差系数 2 ]

Principal point: cc_right = [ 683.51167 351.73864 ] ? [ 7.07742 6.92186 ] //参数含义：[ cc_ right _x cc_ right _y ] ? [ 误差系数 1 误差系数 2 ]

Skew: alpha_c_right = [ 0.00000 ] ? [ 0.00000 ] => angle of pixel axes = 90.00000 ? 0.00000 degrees

Distortion: kc_right = [ 0.09453 -0.41626 -0.00345 -0.00131 0.00000 ] ? [ 0.03354 0.43430 0.00207 0.00223 0.00000 ]

//参数含义：[kc_ right _01, kc_ right _02, kc_ right _03, kc_ right _04, kc_ right _05] ? [ 误差系数 1 ~ 误差系数 5 ]

Extrinsic parameters (position of right camera wrt left camera):

Rotation vector: om = [ -0.01579 -0.00732 -0.00760 ] ? [ 0.00631 0.00675 0.00023 ] //参数含义：[rec_01, rec_02, rec_03] ? [误差系数 1 ~ 误差系数 3]

Translation vector: T = [ -28.14586 0.02818 -0.24377 ] ? [ 0.16493 0.15904 1.11454 ] //参数含义：[T_01, T_02, T_03] ? [误差系数 1 ~ 误差系数 3]