estimate_K_ax – Estimate internal camera parameters from homography between two image

Usage:

```
[K, f_length, fval] = estimate_K_ax(P)
```

Input:

R: 3x3 Homography Matrix

Output:

K - Calibration matrix of the form

```
|   a   0    0  |
|   0   a    0  |
|   0   0    1  |
```

Where:
a = focal length of the camera (the pixels are supposed to be squared, i.e. ax=ay)

f_length - focal length of the camera

fval - minimum value of the function found by the minimization algorithm. The function that is minimized is
D=inv(K)*P*K*(inv(K)*P*K)'-I

Where:
K = Calibration Matrix
P = Homography Matrix
I = Identity Matrix