Q1
Calibrated camera parameters:
camL =

scalar structure containing the fields:

f = 5.5039e+06
R =

0.674225 -0.466420 -0.572603
-0.737278 -0.470153 -0.485158
-0.042923 0.749273 -0.660869

t =

-1.2436e+05
-1.0537e+05
-1.4354e+05

c =

800
600

camR =

scalar structure containing the fields:

f = 6.1257e+06
R =

0.904801 -0.253481 -0.342173
-0.422932 -0.628570 -0.652708
-0.049630 0.735287 -0.675936

t =

-8.2146e+04
-1.5671e+05
-1.6228e+05

c =

800
600

The length of the baseline is: 6.9058e+04 cm

Q2

The average error is:
E = [0.68890;
0.70819;
0.70203]
I believe this error comes from the bad initial conditions. The local search algorithm might stuck in a local minimum.

Q3
w = 5.75 mm
iw = 1600 px
r = 5.75mm/1600px

camL.f = 5.5039e+06 px
f = camL.f * r = 1978 mm

No, this calibration result is off.