

- After fixed the [pattern](#) on rigid place, first calibration process is to capture images. Calibration image pairs in different poses. To take pictures you can use this [code](#).



- We have used camera calibration individually for precalibration of stereo camera calibration to get camera intrinsic matrices and distortion coefficients.
- « Due to the high dimensionality of the parameter space and noise in the input data, the function can diverge from the correct solution. If the intrinsic parameters can be estimated with high accuracy for each of the cameras individually (for example, using **calibrateCamera()** ), you are recommended to do so and then pass **CV\_CALIB\_FIX\_INTRINSIC** flag to the function along with the computed intrinsic parameters. Otherwise, if all the parameters are estimated at once, it makes sense to restrict some parameters.»

