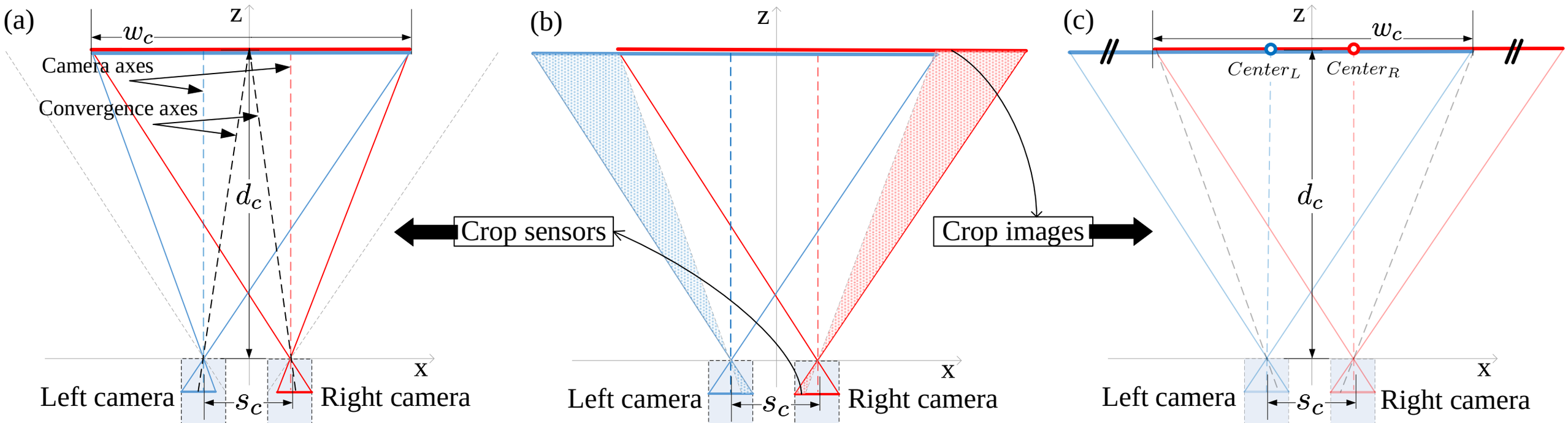
(a)
z
w_c
Camera axes
Convergence axes
d_c
x
Left camera
s_c
Right camera
Crop sensors
(b)
z
x
Left camera
s_c
Right camera
Crop images
(c)
z
w_c
$Center_L$
$Center_R$
d_c
x
Left camera
s_c
Right camera