Camera parameters

Camera 1 (Frame1):

Intrinsic matrix:

[[1.02408777e+03, 0., 6.01806702e+02],

[0., 1.02389478e+03, 5.08131683e+02],

[0., 0., 1.]]

Distortion: [-2.52257544e-03, 4.38565714e-03, 0., 0., 9.21500759e-05]

Camera 2 (Frame2):

Intrinsic matrix:

[[1.02419836e+03, 0., 6.96750427e+02],

[0., 1.02398749e+03, 5.07494263e+02],

[0., 0., 1.]]

Distortion: [-3.26306466e-03, 5.70008671e-03, 0., 0., 7.57322850e-05]

Transformation between cameras (from Camera 1 to 2):

R_vec:

[[9.99999404e-01, -1.24090354e-06, -1.11142127e-03],

[1.29263049e-06, 1., 4.65405355e-05],

[1.11142127e-03, -4.65419434e-05, 9.99999404e-01]]

T_vec = [[-4.34818459e+00],

[2.83603016e-02],

[-9.00963729e-04]] [mm]

The distortion coefficient vectors are defined as [k1, k2, p1, p2, k3] where k_n are the radial distortion coefficients and p_n are the tangential distortion coefficients.