Camera 1 (Frame1):

Intrinsic matrix:

[[497.77777778 0. 319.5]

[0. 497.77777778 239.5]

[0. 0. 1.]]

Extrinsic matrix (this is the rotation and translation of Camera 1 with respect to the world coordinate system):

[4.99999970e-01 -8.66025448e-01 3.65002428e-08 4.22845910e+00;

3.65002428e-08 4.60305181e-08 -1.00000012e+00 2.00000055e+00;

8.66025448e-01 5.00000060e-01 8.81773659e-08 7.43200231e+00];

Distortion:

[0.0, 0.0, 0.0, 0.0, 0.0]

Camera 2 (Frame2):

Intrinsic matrix:

[[497.77777778 0. 319.5]

[0. 497.77777778 239.5]

[0. 0. 1.]]

Extrinsic matrix (this is the rotation and translation of Camera 2 with respect to the world coordinate system):

[5.73576510e-01 -8.19151998e-01 3.73847122e-08 4.61136417e+00;

3.73847122e-08 -2.02285122e-09 -1.00000000e+00 2.00000031e+00;

8.19151998e-01 5.73576510e-01 3.68996460e-08 7.04791103e+00];

Distortion:

[0.0, 0.0, 0.0, 0.0, 0.0]

Transformation between cameras:

R_vec:

[9.96194713e-01 -5.41550256e-08 8.71558063e-02

-1.60560472e-08 1.00000012e+00 -5.68126794e-08

-8.71558795e-02 1.94016203e-08 9.96194765e-01]

T_vec = [-2.48746482e-01 1.28814475e-08 1.27242718e-02]

The above transformations are from Camera 1 to Camera 2 and have been estimated using the following equations:

$$R_{vec} = R_2 * R_1^T$$
$$T_{vec} = T_2 - R_2 * R_1^T * T_1 = T_2 - R_{vec} * T_1$$