



$${}_{img}T_{points} = \underbrace{{}_{img}T_{cam\ pose}}_{\text{"coordinate flip"}} \underbrace{{}_{cam\ pose}T_{world}}_{\text{inverse of cam pose}} \underbrace{{}_{world}T_{points}}_{\text{point coords in world}}$$

$$\begin{bmatrix} 1 & 0 & 0 & 1 \\ 0 & 1 & 0 & -5 \\ 0 & 0 & 1 & 2 \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 1 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \cdot \begin{bmatrix} 1 & 0 & 0 & 2 \\ 0 & 1 & 0 & 1 \\ 0 & 0 & 1 & 5 \\ 0 & 0 & 0 & 1 \end{bmatrix}$$