## ARVR CT-1 Numericals: Prajwal Sundar

2 (a) Let the object be notated at angle of m clock wise angle of m clock wise direction about (
$$x_p$$
,  $y_p$ ) steps to perform;

1 perform translation with  $tx = -x_p$  ty  $= -y_p$ 

2 perform notation with  $tx = -x_p$  ty  $= -y_p$ 

3 perform inverse translation with  $tx = x_p$  ty  $= y_p$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot R - T \cdot P$ 
 $p^2 = -\frac{1}{2} \cdot$ 

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & (-x_{1}\cos \theta - y_{1}\sin \theta + x_{1}) \\ -\sin \theta & \cos \theta & (x_{1}\cos \theta - y_{1}\cos \theta + y_{2}) \\ -\sin \theta & \cos \theta & x_{1}\cos \theta + y_{2}\cos \theta + y_{2}) \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & (-x_{1}\cos \theta - y_{1}\sin \theta + y_{2}\cos \theta + y_{2}) \\ -\sin \theta & \cos \theta & x_{2}\sin \theta + y_{3}\cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & (-x_{1}\cos \theta - y_{1}\sin \theta + y_{2}\cos \theta + y_{2}\cos \theta) \\ -\sin \theta & \cos \theta & x_{2}\sin \theta + y_{3}\cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & (-x_{1}\cos \theta - y_{1}\sin \theta + y_{2}\cos \theta + y_{2}\cos \theta) \\ -\sin \theta & \cos \theta & x_{3}\cos \theta + y_{4}\cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & (-x_{1}\cos \theta - y_{1}\sin \theta + y_{2}\cos \theta + y_{3}\cos \theta) \\ -\sin \theta & \cos \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & (-x_{1}\cos \theta - y_{2}\sin \theta + y_{3}\cos \theta + y_{4}\cos \theta) \\ -\sin \theta & \cos \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & (-x_{1}\cos \theta - y_{2}\sin \theta + y_{3}\cos \theta) \\ -\sin \theta & \cos \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \sin \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

$$P^{3} = \begin{bmatrix} \cos \theta & \cos \theta \\ -\sin \theta & \cos \theta \end{bmatrix}$$

(a) (b) case 1:  
1) Replact about 
$$y = axis$$
 ( $Rx = 0$ )
2) Replact about  $y = -x$  ( $Ry = -x$ )

Thansformation matrix is given by
$$R_2 R_1 = R_2 - x - R_2 = 0$$

$$\begin{cases} 0 & -1 & 0 & 0 \\ -1 & 0 & 0 \\ 0 & 0 & 1 \end{cases} = \begin{cases} -1 & 0 & 0 \\ 0 & 0 & 1 \end{cases} = \begin{cases} 0 & -1 & 0 \\ 0 & 0 & 1 \end{cases}$$

$$cose 2 : Rotate by  $-270^\circ$$$

 $= \text{Rotation by } -270^{\circ} + 360^{\circ} = 90^{\circ}$ reansformation matrix:

since the transformation materies obtained are the same, car 1 = car 2, the transformations are equivalent

Performing transformations with A(1,1) & B(10,10)

$$p'' = \begin{bmatrix} 0 & -1 & 0 \\ 1 & 0 & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 10 \\ 1 & 10 \end{bmatrix} = \begin{bmatrix} -10 \\ 1 & 1 \end{bmatrix}$$

A' = (-1, 1) B' = (-10, 10)

or relified that case 1 = case 2.

Transformed points A' and B' are also obtained successfully.

(2) (c) Reflection about 2y = 91 + 4 9x - 2y = -4  $(-4) + \frac{y}{(2)} = 1$ 

$$\frac{5}{5} \begin{bmatrix} 0 & 0 & 55 \end{bmatrix} \begin{bmatrix} 0 & 0 & 1 & 1 \\ 0 & 0 & 55 \end{bmatrix} \begin{bmatrix} 0 & 0 & 1 & 1 \\ 2 & 1 & -2 \\ -1 & 2 & -4 \\ 0 & 0 & 55 \end{bmatrix} = \frac{1}{5} \begin{bmatrix} 3 & 4 & -8 \\ 4 & -3 & 16 \\ 0 & 0 & 55 \end{bmatrix}$$

Given points:

$$A(6, 3, 3) = A(201, 1)$$

$$B(3, 2, 1) = B(3, 2, 1)$$

$$C(2,4, 2) = C(1, 2, 1)$$

performing the toansformation

or = m. P

$$\rho^{2} = \frac{1}{5} \begin{bmatrix} 3 & 4 & -8 \\ 4 & -3 & 16 \\ 0 & 0 & 5 \end{bmatrix} \begin{bmatrix} 2 & 3 & 1 \\ 1 & 2 & 2 \\ 1 & 1 & 1 \end{bmatrix}$$

$$\hat{p} = \begin{bmatrix} 2 & 9 & 3 \\ 21 & 22 & 14 \\ 5 & 5 & 5 \end{bmatrix}$$

$$p^{2} = \begin{cases} 2/5 & 9/5 & 3/5 \\ 21/5 & 22/5 & 14/5 \\ 1 & 1 & 1 \end{cases}$$

a ind begangle has coordinates

seplected to early has considerated

A!  $\left(\frac{2}{5}, \frac{21}{5}, 1\right)$ B!  $\left(\frac{9}{5}, \frac{29}{5}, 1\right)$ C!  $\left(\frac{3}{5}, \frac{14}{5}, 1\right)$ Example has considerated of soldinates of example of soldinates of example of the reflected plants.