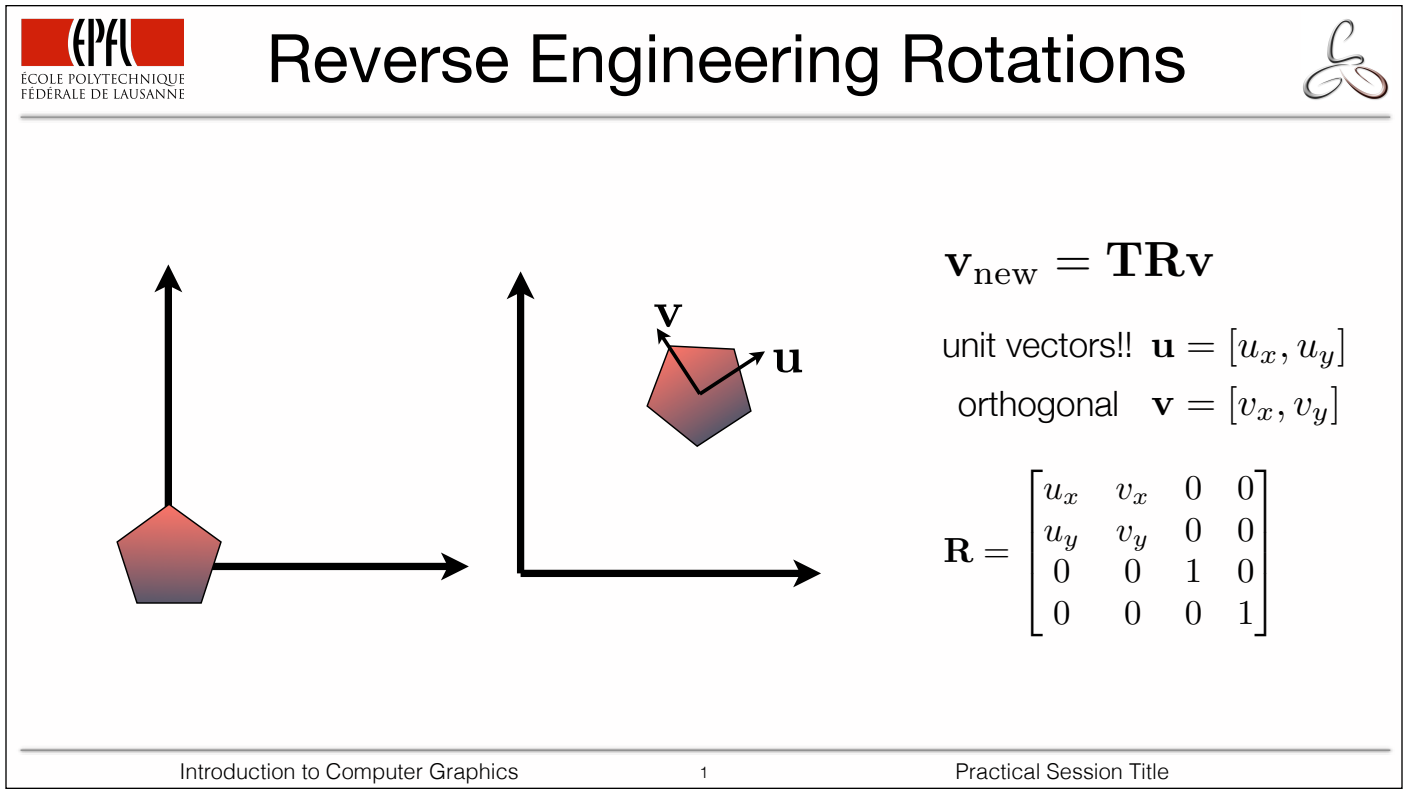

(assumption: we are working with homogeneous coordinates)
We want to obtain the transformation shown above. You already know how to compute the translation **T**, but what about rotation? This can be done by constructing a rotation matrix as shown in the slide. **Note {u,v} need to be normalized and orthogonal to each other!!!**