```
import sympy as sp
from pymuvs.se3 import rot_x, rot_y, rot_z

phi, theta, psi = sp.symbols('ϕ θ ψ')
T = rot_z(psi) @ rot_y(theta) @ rot_x(phi)
```

```
SE3(rotation=Matrix([
    [cos(θ)*cos(ψ), sin(θ)*sin(ϕ)*cos(ψ) - sin(ψ)*cos(ϕ), sin(θ)*cos(ψ)*cos(ϕ) + sin(ψ)*sin(ϕ)],
    [sin(ψ)*cos(θ), sin(θ)*sin(ψ)*sin(ϕ) + cos(ψ)*cos(ϕ), sin(θ)*sin(ψ)*cos(ϕ) - sin(ϕ)*cos(ψ)],
    [      -sin(θ),                       sin(ϕ)*cos(θ),                       cos(θ)*cos(ϕ)]]),
translation=Matrix([[0], [0], [0]])
)
```