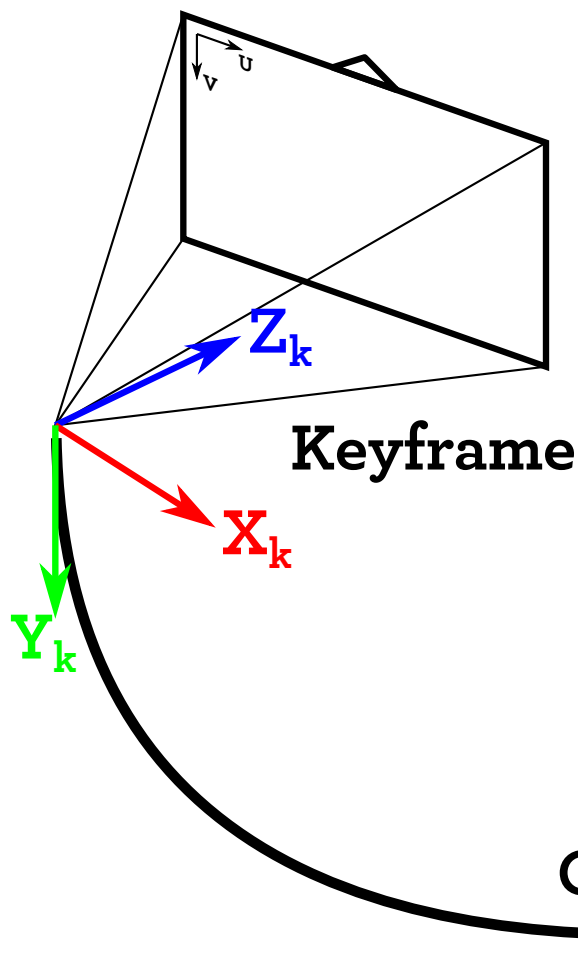


WORLD

in meters/unitless
right-handed coordinate system



$$P_c = R_{kc} * P_k + T_{kc}$$
$$P_c, P_k = \begin{bmatrix} X \\ Y \\ Z \end{bmatrix} \quad T_{kc} = \begin{bmatrix} T_x \\ T_y \\ T_z \end{bmatrix}$$

$R_{kc} = \text{TODO}$
(3x3 rotation Matrix)
angle2dcm(alpha, beta, gamma)

$$T_{kc} = [T_x \ T_y \ T_z \ T_{\alpha} \ T_{\beta} \ T_{\gamma}]$$

CAMERA

in pixels, starting at [1,1]

