WORLD

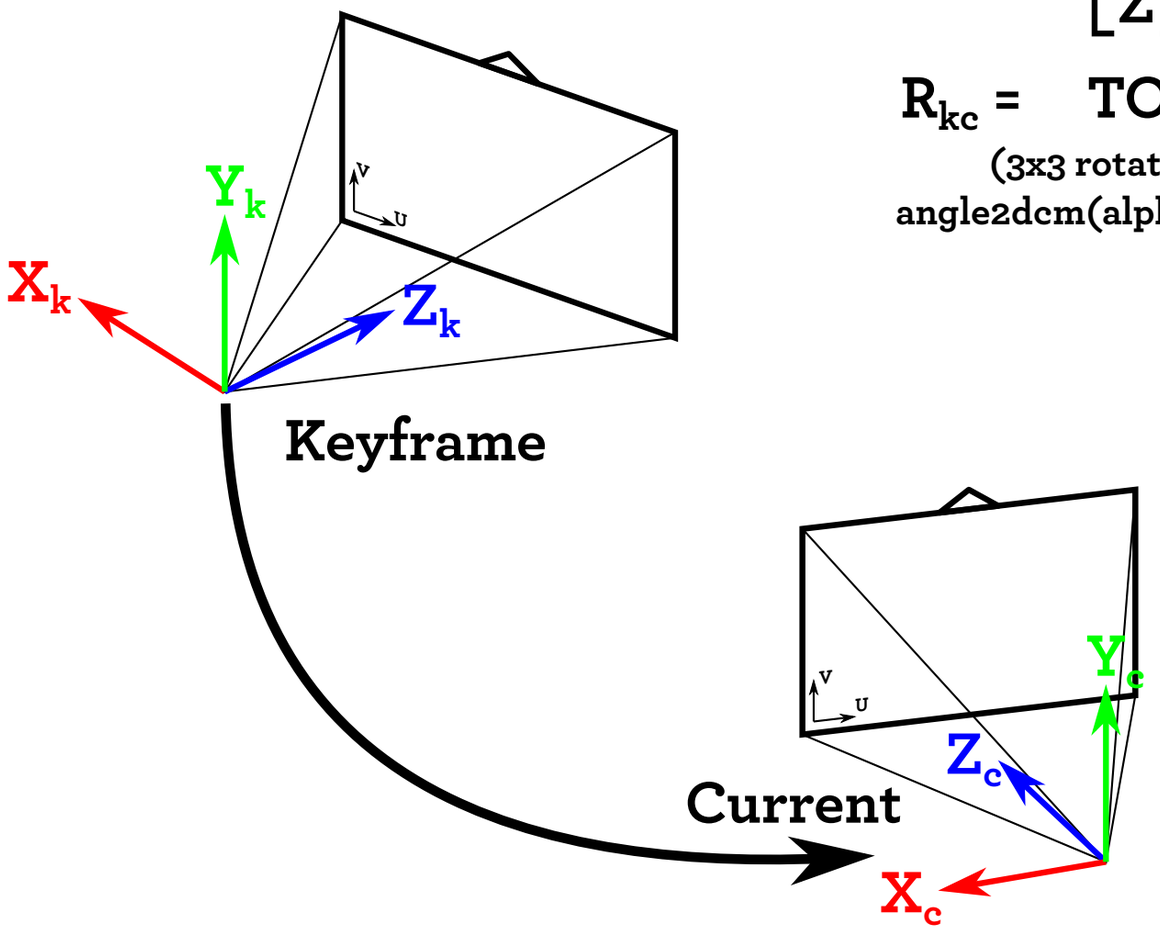
in meters/unitless
right-handed coordinate system

$$P_c = R_{kc} * P_k + T_{kc}$$

$$P_c, P_k = \begin{bmatrix} X \\ Y \\ Z \end{bmatrix} \quad T_{kc} = \begin{bmatrix} T_X \\ T_Y \\ T_Z \end{bmatrix}$$

R_{kc} = TODO

(3x3 rotation Matrix)
angle2dcm(alpha, beta, gamma)

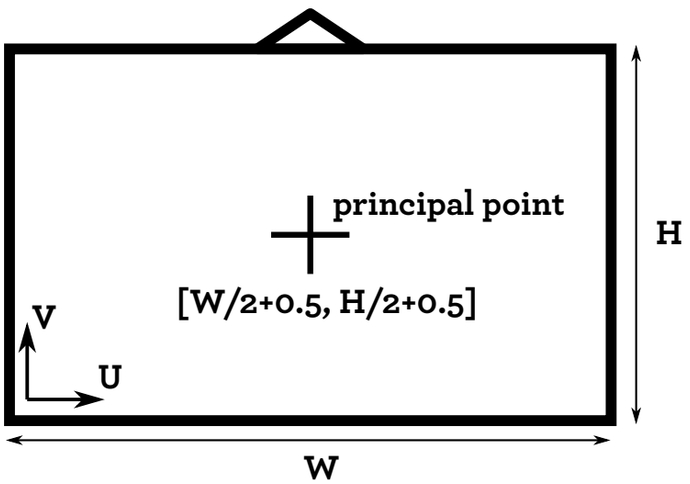


$$T_{kc} = [T_x\ T_y\ T_z\ T_{alpha}\ T_{beta}\ T_{gamma}]$$

CAMERA

in pixels, starting at [1,1]

chose one:
- congruency with computer vision literature
- nice code without random minus-signs
- 1:1 compatibility with Blender



principal point: [3.5, 2.5]