```
>> compute_extrinsics(cad_model, 0, 0)

T_ximea_tilt =

[ cos(pitch_ximea_tilt)*cos(yaw_ximea_tilt), cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt)↙
*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin(yaw_ximea_tilt), sin(roll_ximea_tilt)↙
*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt),↙
x_ximea_tilt]
[ cos(pitch_ximea_tilt)*sin(yaw_ximea_tilt), cos(roll_ximea_tilt)*cos(yaw_ximea_tilt) +↙
sin(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin(yaw_ximea_tilt), cos(roll_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(yaw_ximea_tilt) - cos(yaw_ximea_tilt)*sin(roll_ximea_tilt),↙
y_ximea_tilt]
[                    -sin(pitch_ximea_tilt),↙
cos(pitch_ximea_tilt)*sin(roll_ximea_tilt),↙
cos(pitch_ximea_tilt)*cos(roll_ximea_tilt), z_ximea_tilt]
[                                         0,↙
0,↙
0,            1]


T_tilt_pan =

[  cos(pitch_tilt_pan), 0, sin(pitch_tilt_pan), x_tilt_pan]
[                    0, 1,                   0, y_tilt_pan]
[ -sin(pitch_tilt_pan), 0, cos(pitch_tilt_pan), z_tilt_pan]
[                    0, 0,                   0,          1]


T_pan_base =

[ cos(yaw_pan_base), -sin(yaw_pan_base), 0, 0]
[ sin(yaw_pan_base),  cos(yaw_pan_base), 0, 0]
[                 0,                  0, 1, 0]
[                 0,                  0, 0, 1]


T_base_imperx =

[ cos(pitch_base_imperx)*cos(yaw_base_imperx), cos(yaw_base_imperx)*sin↙
(pitch_base_imperx)*sin(roll_base_imperx) - cos(roll_base_imperx)*sin(yaw_base_imperx),↙
sin(roll_base_imperx)*sin(yaw_base_imperx) + cos(roll_base_imperx)*cos(yaw_base_imperx)↙
*sin(pitch_base_imperx), x_base_imperx]
[ cos(pitch_base_imperx)*sin(yaw_base_imperx), cos(roll_base_imperx)*cos(yaw_base_imperx)↙
+ sin(pitch_base_imperx)*sin(roll_base_imperx)*sin(yaw_base_imperx), cos↙
(roll_base_imperx)*sin(pitch_base_imperx)*sin(yaw_base_imperx) - cos(yaw_base_imperx)*sin↙
(roll_base_imperx), y_base_imperx]
[                     -sin(pitch_base_imperx),↙
cos(pitch_base_imperx)*sin(roll_base_imperx),↙
cos(pitch_base_imperx)*cos(roll_base_imperx), z_base_imperx]
[                                          0,↙
0,↙
```

```
0,             1]


T_ximea_imperx =

[ cos(pitch_base_imperx)*sin(yaw_base_imperx)*(sin(yaw_pan_base)*(sin(pitch_tilt_pan)*↙
(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin↙
(pitch_ximea_tilt)) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos(yaw_ximea_tilt)) -↙
cos(yaw_pan_base)*(cos(roll_ximea_tilt)*sin(yaw_ximea_tilt) - cos(yaw_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(roll_ximea_tilt))) - cos(pitch_base_imperx)*cos(yaw_base_imperx)*↙
(cos(yaw_pan_base)*(sin(pitch_tilt_pan)*(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos↙
(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) - cos(pitch_tilt_pan)*cos↙
(pitch_ximea_tilt)*cos(yaw_ximea_tilt)) + sin(yaw_pan_base)*(cos(roll_ximea_tilt)*sin↙
(yaw_ximea_tilt) - cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt)*sin(roll_ximea_tilt))) - sin↙
(pitch_base_imperx)*(cos(pitch_tilt_pan)*(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos↙
(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) + cos(pitch_ximea_tilt)*cos↙
(yaw_ximea_tilt)*sin(pitch_tilt_pan)),   (cos(yaw_pan_base)*(sin(pitch_tilt_pan)*(sin↙
(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin↙
(pitch_ximea_tilt)) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos(yaw_ximea_tilt)) +↙
sin(yaw_pan_base)*(cos(roll_ximea_tilt)*sin(yaw_ximea_tilt) - cos(yaw_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(roll_ximea_tilt)))*(cos(roll_base_imperx)*sin(yaw_base_imperx) -↙
cos(yaw_base_imperx)*sin(pitch_base_imperx)*sin(roll_base_imperx)) + (sin(yaw_pan_base)*↙
(sin(pitch_tilt_pan)*(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos↙
(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos↙
(yaw_ximea_tilt)) - cos(yaw_pan_base)*(cos(roll_ximea_tilt)*sin(yaw_ximea_tilt) - cos↙
(yaw_ximea_tilt)*sin(pitch_ximea_tilt)*sin(roll_ximea_tilt)))*(cos(roll_base_imperx)*cos↙
(yaw_base_imperx) + sin(pitch_base_imperx)*sin(roll_base_imperx)*sin(yaw_base_imperx)) +↙
cos(pitch_base_imperx)*sin(roll_base_imperx)*(cos(pitch_tilt_pan)*(sin(roll_ximea_tilt)↙
*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) +↙
cos(pitch_ximea_tilt)*cos(yaw_ximea_tilt)*sin(pitch_tilt_pan)), cos(pitch_base_imperx)↙
*cos(roll_base_imperx)*(cos(pitch_tilt_pan)*(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) +↙
cos(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) + cos(pitch_ximea_tilt)↙
*cos(yaw_ximea_tilt)*sin(pitch_tilt_pan)) - (sin(yaw_pan_base)*(sin(pitch_tilt_pan)*(sin↙
(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin↙
(pitch_ximea_tilt)) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos(yaw_ximea_tilt)) -↙
cos(yaw_pan_base)*(cos(roll_ximea_tilt)*sin(yaw_ximea_tilt) - cos(yaw_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(roll_ximea_tilt)))*(cos(yaw_base_imperx)*sin(roll_base_imperx) -↙
cos(roll_base_imperx)*sin(pitch_base_imperx)*sin(yaw_base_imperx)) - (cos(yaw_pan_base)*↙
(sin(pitch_tilt_pan)*(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos↙
(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos↙
(yaw_ximea_tilt)) + sin(yaw_pan_base)*(cos(roll_ximea_tilt)*sin(yaw_ximea_tilt) - cos↙
(yaw_ximea_tilt)*sin(pitch_ximea_tilt)*sin(roll_ximea_tilt)))*(sin(roll_base_imperx)*sin↙
(yaw_base_imperx) + cos(roll_base_imperx)*cos(yaw_base_imperx)*sin(pitch_base_imperx)),↙
x_ximea_tilt - x_base_imperx*(cos(yaw_pan_base)*(sin(pitch_tilt_pan)*(sin↙
(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin↙
(pitch_ximea_tilt)) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos(yaw_ximea_tilt)) +↙
sin(yaw_pan_base)*(cos(roll_ximea_tilt)*sin(yaw_ximea_tilt) - cos(yaw_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(roll_ximea_tilt))) + y_base_imperx*(sin(yaw_pan_base)*(sin↙
(pitch_tilt_pan)*(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos↙
(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos↙
(yaw_ximea_tilt)) - cos(yaw_pan_base)*(cos(roll_ximea_tilt)*sin(yaw_ximea_tilt) - cos↙
```

```
(yaw_ximea_tilt)*sin(pitch_ximea_tilt)*sin(roll_ximea_tilt))) - y_tilt_pan*(cos↙
(roll_ximea_tilt)*sin(yaw_ximea_tilt) - cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt)*sin↙
(roll_ximea_tilt)) + z_tilt_pan*(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos↙
(roll_ximea_tilt)*cos(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) + z_base_imperx*(cos↙
(pitch_tilt_pan)*(sin(roll_ximea_tilt)*sin(yaw_ximea_tilt) + cos(roll_ximea_tilt)*cos↙
(yaw_ximea_tilt)*sin(pitch_ximea_tilt)) + cos(pitch_ximea_tilt)*cos(yaw_ximea_tilt)*sin↙
(pitch_tilt_pan)) + x_tilt_pan*cos(pitch_ximea_tilt)*cos(yaw_ximea_tilt)]
[ sin(pitch_base_imperx)*(cos(pitch_tilt_pan)*(cos(yaw_ximea_tilt)*sin(roll_ximea_tilt) -↙
cos(roll_ximea_tilt)*sin(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) - cos(pitch_ximea_tilt)↙
*sin(pitch_tilt_pan)*sin(yaw_ximea_tilt)) + cos(pitch_base_imperx)*cos(yaw_base_imperx)*↙
(cos(yaw_pan_base)*(sin(pitch_tilt_pan)*(cos(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos↙
(roll_ximea_tilt)*sin(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + cos(pitch_tilt_pan)*cos↙
(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + sin(yaw_pan_base)*(cos(roll_ximea_tilt)*cos↙
(yaw_ximea_tilt) + sin(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin(yaw_ximea_tilt))) - cos↙
(pitch_base_imperx)*sin(yaw_base_imperx)*(sin(yaw_pan_base)*(sin(pitch_tilt_pan)*(cos↙
(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin(pitch_ximea_tilt)*sin↙
(yaw_ximea_tilt)) + cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) - cos↙
(yaw_pan_base)*(cos(roll_ximea_tilt)*cos(yaw_ximea_tilt) + sin(pitch_ximea_tilt)*sin↙
(roll_ximea_tilt)*sin(yaw_ximea_tilt))), - (cos(roll_base_imperx)*cos(yaw_base_imperx) +↙
sin(pitch_base_imperx)*sin(roll_base_imperx)*sin(yaw_base_imperx))*(sin(yaw_pan_base)*↙
(sin(pitch_tilt_pan)*(cos(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*sin↙
(yaw_ximea_tilt)) - cos(yaw_pan_base)*(cos(roll_ximea_tilt)*cos(yaw_ximea_tilt) + sin↙
(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin(yaw_ximea_tilt))) - (cos(roll_base_imperx)↙
*sin(yaw_base_imperx) - cos(yaw_base_imperx)*sin(pitch_base_imperx)*sin↙
(roll_base_imperx))*(cos(yaw_pan_base)*(sin(pitch_tilt_pan)*(cos(yaw_ximea_tilt)*sin↙
(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + cos↙
(pitch_tilt_pan)*cos(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + sin(yaw_pan_base)*(cos↙
(roll_ximea_tilt)*cos(yaw_ximea_tilt) + sin(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin↙
(yaw_ximea_tilt))) - cos(pitch_base_imperx)*sin(roll_base_imperx)*(cos(pitch_tilt_pan)*↙
(cos(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin(pitch_ximea_tilt)↙
*sin(yaw_ximea_tilt)) - cos(pitch_ximea_tilt)*sin(pitch_tilt_pan)*sin(yaw_ximea_tilt)),↙
(sin(roll_base_imperx)*sin(yaw_base_imperx) + cos(roll_base_imperx)*cos(yaw_base_imperx)↙
*sin(pitch_base_imperx))*(cos(yaw_pan_base)*(sin(pitch_tilt_pan)*(cos(yaw_ximea_tilt)*sin↙
(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + cos↙
(pitch_tilt_pan)*cos(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + sin(yaw_pan_base)*(cos↙
(roll_ximea_tilt)*cos(yaw_ximea_tilt) + sin(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin↙
(yaw_ximea_tilt))) + (cos(yaw_base_imperx)*sin(roll_base_imperx) - cos(roll_base_imperx)↙
*sin(pitch_base_imperx)*sin(yaw_base_imperx))*(sin(yaw_pan_base)*(sin(pitch_tilt_pan)*↙
(cos(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin(pitch_ximea_tilt)↙
*sin(yaw_ximea_tilt)) + cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) -↙
cos(yaw_pan_base)*(cos(roll_ximea_tilt)*cos(yaw_ximea_tilt) + sin(pitch_ximea_tilt)*sin↙
(roll_ximea_tilt)*sin(yaw_ximea_tilt))) - cos(pitch_base_imperx)*cos(roll_base_imperx)*↙
(cos(pitch_tilt_pan)*(cos(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) - cos(pitch_ximea_tilt)*sin(pitch_tilt_pan)*sin↙
(yaw_ximea_tilt)), y_ximea_tilt + y_tilt_pan*(cos(roll_ximea_tilt)*cos(yaw_ximea_tilt) +↙
sin(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin(yaw_ximea_tilt)) - z_tilt_pan*(cos↙
(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin(pitch_ximea_tilt)*sin↙
(yaw_ximea_tilt)) + x_base_imperx*(cos(yaw_pan_base)*(sin(pitch_tilt_pan)*(cos↙
(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin(pitch_ximea_tilt)*sin↙
(yaw_ximea_tilt)) + cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + sin↙
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```
(yaw_pan_base)*(cos(roll_ximea_tilt)*cos(yaw_ximea_tilt) + sin(pitch_ximea_tilt)*sin↙
(roll_ximea_tilt)*sin(yaw_ximea_tilt))) - y_base_imperx*(sin(yaw_pan_base)*(sin↙
(pitch_tilt_pan)*(cos(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) + cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*sin↙
(yaw_ximea_tilt)) - cos(yaw_pan_base)*(cos(roll_ximea_tilt)*cos(yaw_ximea_tilt) + sin↙
(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin(yaw_ximea_tilt))) - z_base_imperx*(cos↙
(pitch_tilt_pan)*(cos(yaw_ximea_tilt)*sin(roll_ximea_tilt) - cos(roll_ximea_tilt)*sin↙
(pitch_ximea_tilt)*sin(yaw_ximea_tilt)) - cos(pitch_ximea_tilt)*sin(pitch_tilt_pan)*sin↙
(yaw_ximea_tilt)) + x_tilt_pan*cos(pitch_ximea_tilt)*sin(yaw_ximea_tilt)]
[↙
sin(pitch_base_imperx)*(sin(pitch_tilt_pan)*sin(pitch_ximea_tilt) - cos(pitch_tilt_pan)↙
*cos(pitch_ximea_tilt)*cos(roll_ximea_tilt)) - cos(pitch_base_imperx)*cos↙
(yaw_base_imperx)*(cos(yaw_pan_base)*(cos(pitch_tilt_pan)*sin(pitch_ximea_tilt) + cos↙
(pitch_ximea_tilt)*cos(roll_ximea_tilt)*sin(pitch_tilt_pan)) - cos(pitch_ximea_tilt)*sin↙
(roll_ximea_tilt)*sin(yaw_pan_base)) + cos(pitch_base_imperx)*sin(yaw_base_imperx)*(sin↙
(yaw_pan_base)*(cos(pitch_tilt_pan)*sin(pitch_ximea_tilt) + cos(pitch_ximea_tilt)*cos↙
(roll_ximea_tilt)*sin(pitch_tilt_pan)) + cos(pitch_ximea_tilt)*cos(yaw_pan_base)*sin↙
(roll_ximea_tilt)),↙
(sin(yaw_pan_base)*(cos(pitch_tilt_pan)*sin(pitch_ximea_tilt) + cos(pitch_ximea_tilt)*cos↙
(roll_ximea_tilt)*sin(pitch_tilt_pan)) + cos(pitch_ximea_tilt)*cos(yaw_pan_base)*sin↙
(roll_ximea_tilt))*(cos(roll_base_imperx)*cos(yaw_base_imperx) + sin(pitch_base_imperx)↙
*sin(roll_base_imperx)*sin(yaw_base_imperx)) + (cos(yaw_pan_base)*(cos(pitch_tilt_pan)↙
*sin(pitch_ximea_tilt) + cos(pitch_ximea_tilt)*cos(roll_ximea_tilt)*sin(pitch_tilt_pan))↙
- cos(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin(yaw_pan_base))*(cos(roll_base_imperx)↙
*sin(yaw_base_imperx) - cos(yaw_base_imperx)*sin(pitch_base_imperx)*sin↙
(roll_base_imperx)) - cos(pitch_base_imperx)*sin(roll_base_imperx)*(sin(pitch_tilt_pan)↙
*sin(pitch_ximea_tilt) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos(roll_ximea_tilt)),↙
- (sin(yaw_pan_base)*(cos(pitch_tilt_pan)*sin(pitch_ximea_tilt) + cos(pitch_ximea_tilt)↙
*cos(roll_ximea_tilt)*sin(pitch_tilt_pan)) + cos(pitch_ximea_tilt)*cos(yaw_pan_base)*sin↙
(roll_ximea_tilt))*(cos(yaw_base_imperx)*sin(roll_base_imperx) - cos(roll_base_imperx)↙
*sin(pitch_base_imperx)*sin(yaw_base_imperx)) - (cos(yaw_pan_base)*(cos(pitch_tilt_pan)↙
*sin(pitch_ximea_tilt) + cos(pitch_ximea_tilt)*cos(roll_ximea_tilt)*sin(pitch_tilt_pan))↙
- cos(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin(yaw_pan_base))*(sin(roll_base_imperx)↙
*sin(yaw_base_imperx) + cos(roll_base_imperx)*cos(yaw_base_imperx)*sin↙
(pitch_base_imperx)) - cos(pitch_base_imperx)*cos(roll_base_imperx)*(sin(pitch_tilt_pan)↙
*sin(pitch_ximea_tilt) - cos(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos(roll_ximea_tilt)),↙
z_ximea_tilt - z_base_imperx*(sin(pitch_tilt_pan)*sin(pitch_ximea_tilt) - cos↙
(pitch_tilt_pan)*cos(pitch_ximea_tilt)*cos(roll_ximea_tilt)) - x_tilt_pan*sin↙
(pitch_ximea_tilt) - x_base_imperx*(cos(yaw_pan_base)*(cos(pitch_tilt_pan)*sin↙
(pitch_ximea_tilt) + cos(pitch_ximea_tilt)*cos(roll_ximea_tilt)*sin(pitch_tilt_pan)) -↙
cos(pitch_ximea_tilt)*sin(roll_ximea_tilt)*sin(yaw_pan_base)) + y_base_imperx*(sin↙
(yaw_pan_base)*(cos(pitch_tilt_pan)*sin(pitch_ximea_tilt) + cos(pitch_ximea_tilt)*cos↙
(roll_ximea_tilt)*sin(pitch_tilt_pan)) + cos(pitch_ximea_tilt)*cos(yaw_pan_base)*sin↙
(roll_ximea_tilt)) + z_tilt_pan*cos(pitch_ximea_tilt)*cos(roll_ximea_tilt) +↙
y_tilt_pan*cos(pitch_ximea_tilt)*sin(roll_ximea_tilt)]
[↙
0,↙
0,↙
0,↙
1]
```

```
ans =

   -0.1964   -0.9794    0.0474    3.1597
    0.5937   -0.1572   -0.7891    0.4304
    0.7803   -0.1268    0.6124    0.3876
         0         0         0    1.0000

>>
```