```
function R = Rodriguez(theta_vector)
    % Function of compute rotation matx using Rodriguez's frm

    % Compute magnitude (angle) and unit vector (rotation)
    theta = norm(theta_vector);  % Magnitude of input
    if theta == 0
        R = eye(3);  % No rotation, return identity matx
        return;
    end
    k = theta_vector / theta;  % Normalize > unit vector

    % Skew-symmetric matx of k
    K = [0    -k(3)  k(2);
         k(3)  0    -k(1);
        -k(2)  k(1)  0];

    % sinc function to handle zero case
    sinc_theta = sinc(theta / pi);  % sinc(theta/pi) to avoid division by zero

    % Rodriguez's frm
    R = eye(3) + sinc_theta * K + ((1 - cos(theta)) / (theta^2)) * (K * K);
end
```