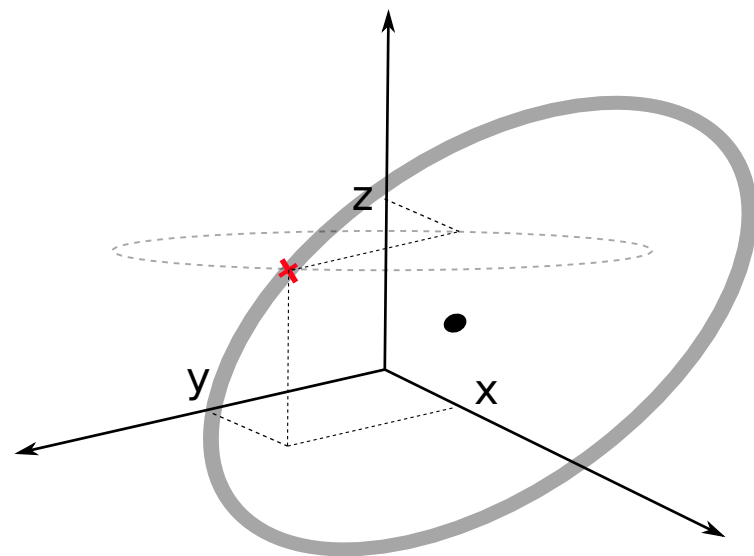


$$X = [x, y, 0]$$

Rotation R et translation



$$X' = [x_c, y_c, z_c] + RX$$