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# **transforms3d Documentation**

***Release 0.4.2***

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This package is a collection of Python functions and classes to create and convert 3-dimensional transformations such as rotations, zooms, shears and reflections.

It is based on [transformations.py](#) by [Christoph Gohlke](#), with some restructuring by [Matthew Brett](#).

Install the latest version with:

```
pip install transforms3d
```



## CONVENTIONS FOR TRANSFORMS

For the transforms we have coded here, we have followed some conventions that are not universal, but seem common enough.

Transformation matrices are matrices for application on the left, applied to coordinates on the right, stored as column vectors.

Let's say you are transforming a set of points. The points are vectors  $v^1, v^2 \dots v^N$ , and the vectors are composed of  $x$ ,  $y$  and  $z$  coordinates, so that  $v^1 = (x^1, y^1, z^1)$ , then your points matrix  $P$  would look like:

$$P = \begin{pmatrix} x^1, x^2, \dots, x^N \\ y^1, y^2, \dots, y^N \\ z^1, z^2, \dots, z^N \end{pmatrix}$$

If we are applying a 3x3 transformation matrix  $M$ , to transform points  $P$ , then the transformed points  $v'$  are given by:

$$v' = M \cdot P$$





## NAMING CONVENTIONS

In the code, we try to abbreviate common concepts in a standard way.

- *aff* - 4 x 4 *affine matrix* for operating on homogenous coordinates of shape (4,) or (4, N);
- *mat* - 3 x 3 transformation matrix for operating on non-homogenous coordinate vectors of shape (3,) or (3, N). A *rotation matrix* is an example of a transformation matrix;
- *euler* - *euler angles* - sequence of three scalars giving rotations about defined axes;
- *axangle* - *axis angle* - axis (vector) and angle (scalar) giving axis around which to rotate and angle of rotation;
- *quat* - *quaternion* - shape (4,);
- *rfnorm* : reflection in plane defined by normal (vector) and optional point (vector);
- *zfdir* : zooms encoded by factor (scalar) and direction (vector);
- *striu* : shears encoded by vector giving triangular portion above diagonal of N x N array (for ND transformation);
- *sadn* : shears encoded by angle scalar, direction vector, normal vector (with optional point vector).



## GIMBAL LOCK

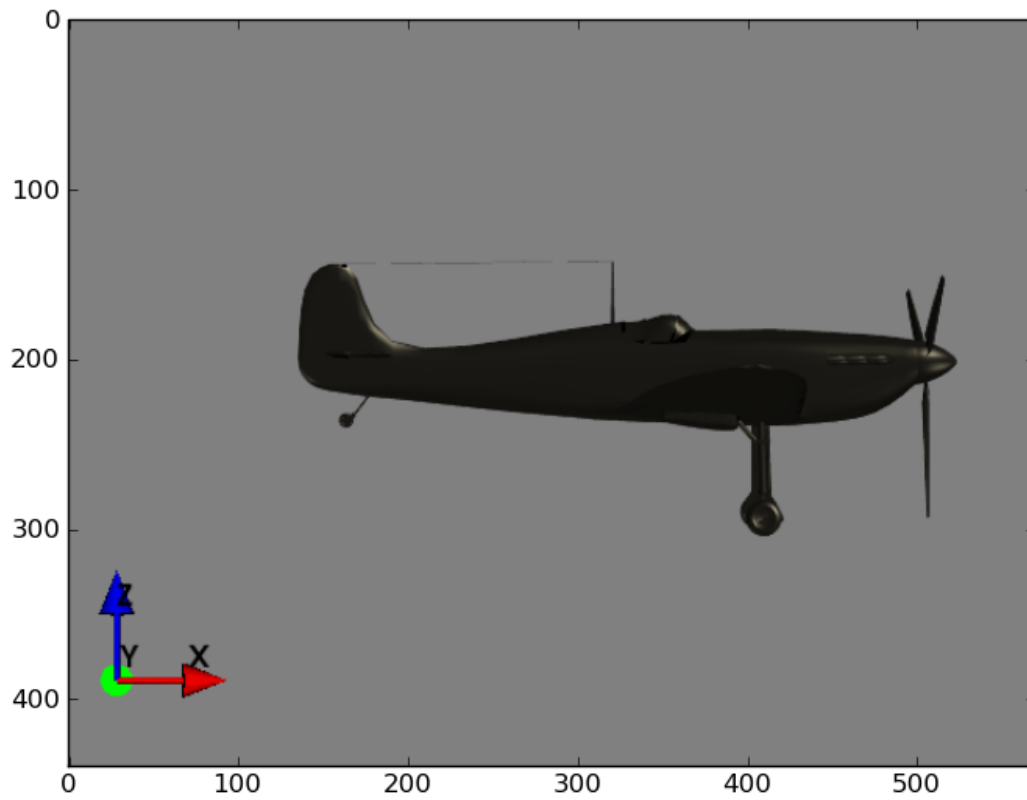
See also: [http://en.wikipedia.org/wiki/Gimbal\\_lock](http://en.wikipedia.org/wiki/Gimbal_lock)

Euler angles have a major deficiency, and that is, that it is possible, in some rotation sequences, to reach a situation where two of the three Euler angles cause rotation around the same axis of the object. In the case below, rotation around the  $x$  axis becomes indistinguishable in its effect from rotation around the  $z$  axis, so the  $z$  and  $x$  axis angles collapse into one transformation, and the rotation reduces from three degrees of freedom to two.

### 3.1 Example

Imagine that we are using the Euler angle convention of starting with a rotation around the  $x$  axis, followed by the  $y$  axis, followed by the  $z$  axis.

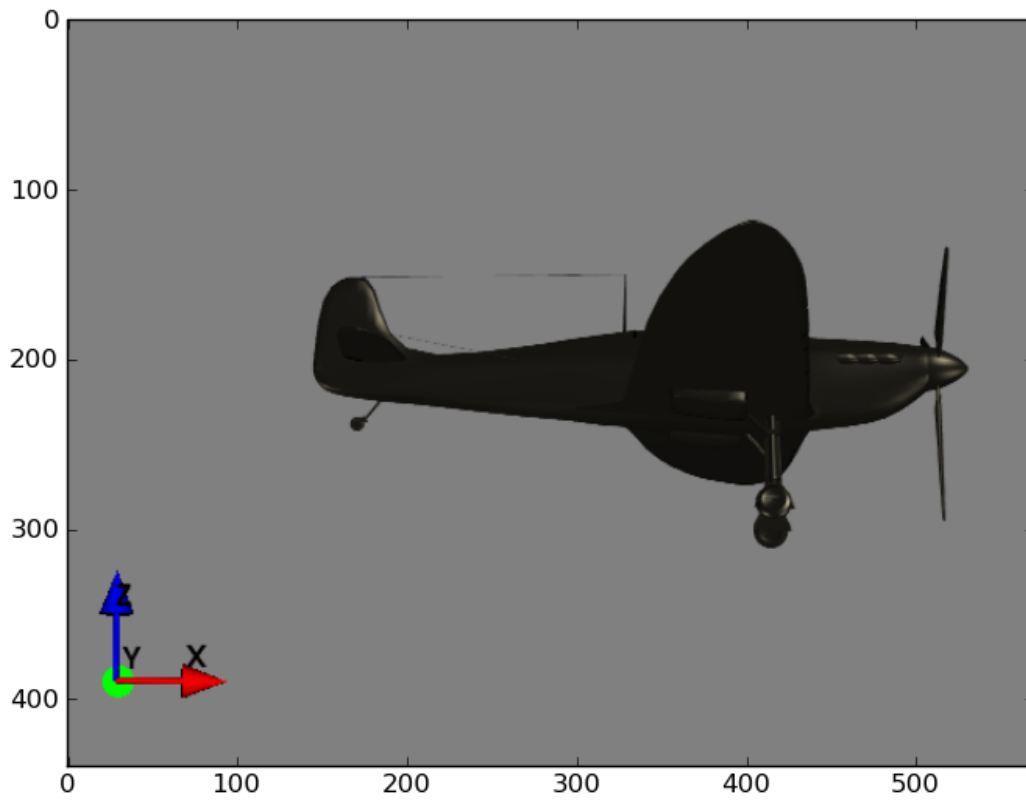
Here we see a Spitfire aircraft, flying across the screen. The  $x$  axis is left to right (tail to nose), the  $y$  axis is from the left wing tip to the right wing tip (going away from the screen), and the  $z$  axis is from bottom to top:



We want to rotate the aircraft to look something like this:



We might start by doing an  $x$  rotation, making a slight roll with the left wing tilting down (rotation about  $x$ ) like this:



Let's say that the x rotation is  $-0.2$  radians.

Then we do a pitch so we are pointing straight up (rotation around  $y$  axis). This is a rotation by  $-\pi/2$  radians.



To get to our desired position from here, we need to do a turn of something like 0.2 radians of the nose towards the viewer (and the tail away from the viewer). All we have left is our  $z$  rotation (rotation around the  $z$  axis. Unfortunately, the current result of a rotation around the  $z$  axis has now become the same as a previous rotation around the  $x$  axis. To see this, look at the result of the rotation around the  $y$  axis. Notice that the  $x$  axis, as was, is now aligned with the  $z$  axis, as it is now. Rotating around the  $z$  axis will have exactly the same effect as adding an extra rotation around the  $x$  axis at the beginning. That means that, when there is a  $y$  axis rotation that rotates the  $x$  axis onto the  $z$  axis (a rotation of  $\pm\pi/2$  around the  $y$  axis) - the  $x$  and  $y$  axes are “locked” together.

This does not mean that we cannot do the rotations we need, only that we can’t do them by starting with the most obvious  $x$  and  $y$  rotations. In fact what we will have to do is first rotate around  $x$  by  $\pi/2 - 0.2$  radians, then do a  $y$  rotation of  $-\pi/2 + 0.2$  radians, and finally a  $z$  rotation of  $-\pi/2$  radians. See the code below for the details.

## 3.2 Mathematics of gimbal lock

See `transforms3d.derivations.eulerangles`.

We see gimbal lock for this type of Euler axis convention, when  $\cos(\beta) = 0$ , where  $\beta$  is the angle of rotation around the  $y$  axis. By “this type of convention” we mean using rotation around all 3 of the  $x$ ,  $y$  and  $z$  axes, rather than using the same axis twice - e.g. the physics convention of  $z$  followed by  $x$  followed by  $z$  axis rotation (the physics convention has different properties to its gimbal lock).

We can show how gimbal lock works by creating a rotation matrix for the three component rotations. Recall that, for a rotation of  $\alpha$  radians around  $x$ , followed by a rotation  $\beta$  around  $y$ , followed by rotation  $\gamma$  around  $z$ , the rotation matrix

$R$  is:

$$R = \begin{bmatrix} \cos(\beta) \cos(\gamma) & \sin(\alpha) \sin(\beta) \cos(\gamma) - \sin(\gamma) \cos(\alpha) & \sin(\alpha) \sin(\gamma) + \sin(\beta) \cos(\alpha) \cos(\gamma) \\ \sin(\gamma) \cos(\beta) & \sin(\alpha) \sin(\beta) \sin(\gamma) + \cos(\alpha) \cos(\gamma) & -\sin(\alpha) \cos(\gamma) + \sin(\beta) \sin(\gamma) \cos(\alpha) \\ -\sin(\beta) & \sin(\alpha) \cos(\beta) & \cos(\alpha) \cos(\beta) \end{bmatrix}$$

In our case the  $y$  rotation  $\beta = -\pi/2$ ,  $\cos(\beta) = 0$ ,  $\sin(\beta) = -1$ :

$$R = \begin{bmatrix} 0 & -\sin(\alpha) \cos(\gamma) - \sin(\gamma) \cos(\alpha) & \sin(\alpha) \sin(\gamma) - \cos(\alpha) \cos(\gamma) \\ 0 & -\sin(\alpha) \sin(\gamma) + \cos(\alpha) \cos(\gamma) & -\sin(\alpha) \cos(\gamma) - \sin(\gamma) \cos(\alpha) \\ 1 & 0 & 0 \end{bmatrix}$$

From the [angle sum and difference identities](#) (see also [geometric proof](#), [Mathworld treatment](#)) we remind ourselves that, for any two angles  $\alpha$  and  $\beta$ :

$$\begin{aligned} \sin(\alpha \pm \beta) &= \sin \alpha \cos \beta \pm \cos \alpha \sin \beta \\ \cos(\alpha \pm \beta) &= \cos \alpha \cos \beta \mp \sin \alpha \sin \beta \end{aligned}$$

We can rewrite  $R$  as:

$$R = \begin{bmatrix} 0 & -W_1 & -W_2 \\ 0 & W_2 & -W_1 \\ 1 & 0 & 0 \end{bmatrix}$$

where:

$$\begin{aligned} W_1 &= \sin(\alpha) \cos(\gamma) + \sin(\gamma) \cos(\alpha) = \sin(\alpha + \gamma) \\ W_2 &= -\sin(\alpha) \sin(\gamma) + \cos(\alpha) \cos(\gamma) = \cos(\alpha + \gamma) \end{aligned}$$

We immediately see that  $\alpha$  and  $\gamma$  are going to lead to the same transformations - the mathematical expression of the observation on the spitfire above, that rotation around the  $x$  axis is equivalent to rotation about the  $z$  axis.

It's easy to do the same set of reductions for the case where  $\sin(\beta) = 1$ ; see <http://www.gregslabaugh.name/publications/euler.pdf>.

### 3.3 The example in code

Here is what our gimbal lock looks like in code:

```
>>> import numpy as np
>>> np.set_printoptions(precision=3, suppress=True) # neat printing
>>> from transforms3d.euler import euler2mat, mat2euler
>>> x_angle = -0.2
>>> y_angle = -np.pi / 2
>>> z_angle = -0.2
>>> R = euler2mat(x_angle, y_angle, z_angle, 'sxyz')
>>> R
array([[ 0.    ,  0.389, -0.921],
       [-0.    ,  0.921,  0.389],
       [ 1.    , -0.    ,  0.    ]])
```

This isn't the transformation we actually want because of the gimbal lock. The gimbal lock means that `x_angle` and `z_angle` result in rotations about the same axis of the object. So, we can add something to the `x_angle` and subtract the same value from `z_angle` to get the same result:



```
>>> R = euler2mat(x_angle + 0.1, y_angle, z_angle - 0.1, 'sxyz')
>>> R
array([[ 0.    ,  0.389, -0.921],
       [-0.    ,  0.921,  0.389],
       [ 1.    , -0.    ,  0.   ]])
```

In fact, we could omit the z rotation entirely and put all the rotation into the original x axis rotation and still get the same rotation matrix:

```
>>> R_dash = euler2mat(x_angle + z_angle, y_angle, 0, 'sxyz')
>>> np.allclose(R, R_dash)
True
```

So, there is no future in doing our transformations starting with this x and y rotation, if we are rotating with this axis order. We can get the transformation we actually want by doing the rotations in the order x, then z then y, like this:

```
>>> R = euler2mat(x_angle, z_angle, y_angle, 'sxzy')
>>> R
array([[ 0.    ,  0.199, -0.98 ],
       [-0.199,  0.961,  0.195],
       [ 0.98 ,  0.195,  0.039]])
```

We can get this same transformation using our original x, y, z rotation order, but using different rotation angles:

```
>>> x_dash, y_dash, z_dash = mat2euler(R, 'sxyz')
>>> np.array((x_dash, y_dash, z_dash)) # np.array for print neatness
array([ 1.371, -1.371, -1.571])
>>> R = euler2mat(x_dash, y_dash, z_dash, 'sxyz')
>>> R
array([[ 0.    ,  0.199, -0.98 ],
       [-0.199,  0.961,  0.195],
       [ 0.98 ,  0.195,  0.039]])
```



## API REFERENCE

### 4.1 transforms3d

transforms3d package

Based on, largely using transformations.py by Christoph Gohlke

Additional code monkey work by Matthew Brett

==

### 4.2 \_gohlketransforms

Homogeneous Transformation Matrices and Quaternions.

A library for calculating 4x4 matrices for translating, rotating, reflecting, scaling, shearing, projecting, orthogonalizing, and superimposing arrays of 3D homogeneous coordinates as well as for converting between rotation matrices, Euler angles, and quaternions. Also includes an Arcball control object and functions to decompose transformation matrices.

**Author**

Christoph Gohlke

**Organization**

Laboratory for Fluorescence Dynamics, University of California, Irvine

**Version**

2017.02.17

#### 4.2.1 Requirements

- CPython 2.7 or 3.5
- Numpy 1.11
- Transformations.c 2017.02.17 (recommended for speedup of some functions)

#### 4.2.2 Notes

The API is not stable yet and is expected to change between revisions.

This Python code is not optimized for speed. Refer to the transformations.c module for a faster implementation of some functions.

Documentation in HTML format can be generated with epydoc.

Matrices (M) can be inverted using `numpy.linalg.inv(M)`, be concatenated using `numpy.dot(M0, M1)`, or transform homogeneous coordinate arrays (v) using `numpy.dot(M, v)` for shape (4, \*) column vectors, respectively `numpy.dot(v, M.T)` for shape (\*, 4) row vectors (“array of points”).

This module follows the “column vectors on the right” and “row major storage” (C contiguous) conventions. The translation components are in the right column of the transformation matrix, i.e. `M[:3, 3]`. The transpose of the transformation matrices may have to be used to interface with other graphics systems, e.g. with OpenGL’s `glMultMatrixd()`. See also [16].

Calculations are carried out with `numpy.float64` precision.

Vector, point, quaternion, and matrix function arguments are expected to be “array like”, i.e. tuple, list, or numpy arrays.

Return types are numpy arrays unless specified otherwise.

Angles are in radians unless specified otherwise.

Quaternions  $w+ix+jy+kz$  are represented as `[w, x, y, z]`.

A triple of Euler angles can be applied/interpreted in 24 ways, which can be specified using a 4 character string or encoded 4-tuple:

*Axes 4-string:* e.g. ‘sxyz’ or ‘ryxy’

- first character : rotations are applied to ‘s’tatic or ‘r’otating frame
- remaining characters : successive rotation axis ‘x’, ‘y’, or ‘z’

*Axes 4-tuple:* e.g. (0, 0, 0, 0) or (1, 1, 1, 1)

- inner axis: code of axis (‘x’:0, ‘y’:1, ‘z’:2) of rightmost matrix.
- parity : even (0) if inner axis ‘x’ is followed by ‘y’, ‘y’ is followed by ‘z’, or ‘z’ is followed by ‘x’. Otherwise odd (1).
- repetition : first and last axis are same (1) or different (0).
- frame : rotations are applied to static (0) or rotating (1) frame.

Other Python packages and modules for 3D transformations and quaternions:

- **Transforms3d**  
includes most code of this module.
- `Blender.mathutils`
- `numpy-dtypes`

## 4.2.3 References

- (1) Matrices and transformations. Ronald Goldman. In “Graphics Gems I”, pp 472-475. Morgan Kaufmann, 1990.
- (2) More matrices and transformations: shear and pseudo-perspective. Ronald Goldman. In “Graphics Gems II”, pp 320-323. Morgan Kaufmann, 1991.
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- (8) A discussion of the solution for the best rotation to relate two sets of vectors. W Kabsch. Acta Cryst. 1978. A34, 827-828.
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- (10) Quaternions. Ken Shoemake. <http://www.sfu.ca/~jwa3/cmpt461/files/quatut.pdf>
- (11) From quaternion to matrix and back. JMP van Waveren. 2005. <http://www.intel.com/cd/ids/developer/asmo-na/eng/293748.htm>
- (12) Uniform random rotations. Ken Shoemake. In "Graphics Gems III", pp 124-132. Morgan Kaufmann, 1992.
- (13) Quaternion in molecular modeling. CFF Karney. J Mol Graph Mod, 25(5):595-604
- (14) New method for extracting the quaternion from a rotation matrix. Itzhack Y Bar-Itzhack, J Guid Contr Dynam. 2000. 23(6): 1085-1087.
- (15) Multiple View Geometry in Computer Vision. Hartley and Zissermann. Cambridge University Press; 2nd Ed. 2004. Chapter 4, Algorithm 4.7, p 130.
- (16) Column Vectors vs. Row Vectors. <http://steve.hollasch.net/cgindex/math/matrix/column-vec.html>

## 4.2.4 Examples

```
>>> alpha, beta, gamma = 0.123, -1.234, 2.345
>>> origin, xaxis, yaxis, zaxis = [0, 0, 0], [1, 0, 0], [0, 1, 0], [0, 0, 1]
>>> I = identity_matrix()
>>> Rx = rotation_matrix(alpha, xaxis)
>>> Ry = rotation_matrix(beta, yaxis)
>>> Rz = rotation_matrix(gamma, zaxis)
>>> R = concatenate_matrices(Rx, Ry, Rz)
>>> euler = euler_from_matrix(R, 'rxyz')
>>> numpy.allclose([alpha, beta, gamma], euler)
True
>>> Re = euler_matrix(alpha, beta, gamma, 'rxyz')
>>> is_same_transform(R, Re)
True
>>> al, be, ga = euler_from_matrix(Re, 'rxyz')
>>> is_same_transform(Re, euler_matrix(al, be, ga, 'rxyz'))
True
>>> qx = quaternion_about_axis(alpha, xaxis)
>>> qy = quaternion_about_axis(beta, yaxis)
>>> qz = quaternion_about_axis(gamma, zaxis)
>>> q = quaternion_multiply(qx, qy)
>>> q = quaternion_multiply(q, qz)
>>> Rq = quaternion_matrix(q)
>>> is_same_transform(R, Rq)
True
>>> S = scale_matrix(1.23, origin)
>>> T = translation_matrix([1, 2, 3])
>>> Z = shear_matrix(beta, xaxis, origin, zaxis)
>>> R = random_rotation_matrix(numpy.random.rand(3))
>>> M = concatenate_matrices(T, R, Z, S)
>>> scale, shear, angles, trans, persp = decompose_matrix(M)
>>> numpy.allclose(scale, 1.23)
True
```

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```

>>> numpy.allclose(trans, [1, 2, 3])
True
>>> numpy.allclose(shear, [0, math.tan(beta), 0])
True
>>> is_same_transform(R, euler_matrix(axes='sxyz', *angles))
True
>>> M1 = compose_matrix(scale, shear, angles, trans, persp)
>>> is_same_transform(M, M1)
True
>>> v0, v1 = random_vector(3), random_vector(3)
>>> M = rotation_matrix(angle_between_vectors(v0, v1), vector_product(v0, v1))
>>> v2 = numpy.dot(v0, M[:3,:3].T)
>>> numpy.allclose(unit_vector(v1), unit_vector(v2))
True

```

<code>Arcball([initial])</code>	Virtual Trackball Control.
<code>affine_matrix_from_points(v0, v1[, shear, ...])</code>	Return affine transform matrix to register two point sets.
<code>angle_between_vectors(v0, v1[, directed, axis])</code>	Return angle between vectors.
<code>arcball_constrain_to_axis(point, axis)</code>	Return sphere point perpendicular to axis.
<code>arcball_map_to_sphere(point, center, radius)</code>	Return unit sphere coordinates from window coordinates.
<code>arcball_nearest_axis(point, axes)</code>	Return axis, which arc is nearest to point.
<code>clip_matrix(left, right, bottom, top, near, far)</code>	Return matrix to obtain normalized device coordinates from frustum.
<code>compose_matrix([scale, shear, angles, ...])</code>	Return transformation matrix from sequence of transformations.
<code>concatenate_matrices(*matrices)</code>	Return concatenation of series of transformation matrices.
<code>decompose_matrix(matrix)</code>	Return sequence of transformations from transformation matrix.
<code>euler_from_matrix(matrix[, axes])</code>	Return Euler angles from rotation matrix for specified axis sequence.
<code>euler_from_quaternion(quaternion[, axes])</code>	Return Euler angles from quaternion for specified axis sequence.
<code>euler_matrix(ai, aj, ak[, axes])</code>	Return homogeneous rotation matrix from Euler angles and axis sequence.
<code>identity_matrix()</code>	Return 4x4 identity/unit matrix.
<code>inverse_matrix(matrix)</code>	Return inverse of square transformation matrix.
<code>is_same_quaternion(q0, q1)</code>	Return True if two quaternions are equal.
<code>is_same_transform(matrix0, matrix1)</code>	Return True if two matrices perform same transformation.
<code>orthogonalization_matrix(lengths, angles)</code>	Return orthogonalization matrix for crystallographic cell coordinates.
<code>projection_from_matrix(matrix[, pseudo])</code>	Return projection plane and perspective point from projection matrix.
<code>projection_matrix(point, normal[, ...])</code>	Return matrix to project onto plane defined by point and normal.
<code>quaternion_about_axis(angle, axis)</code>	Return quaternion for rotation about axis.
<code>quaternion_conjugate(quaternion)</code>	Return conjugate of quaternion.
<code>quaternion_from_euler(ai, aj, ak[, axes])</code>	Return quaternion from Euler angles and axis sequence.
<code>quaternion_from_matrix(matrix[, isprecise])</code>	Return quaternion from rotation matrix.

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Table 2 – continued from previous page

<code>quaternion_imag(quaternion)</code>	Return imaginary part of quaternion.
<code>quaternion_inverse(quaternion)</code>	Return inverse of quaternion.
<code>quaternion_matrix(quaternion)</code>	Return homogeneous rotation matrix from quaternion.
<code>quaternion_multiply(quaternion1, quaternion0)</code>	Return multiplication of two quaternions.
<code>quaternion_real(quaternion)</code>	Return real part of quaternion.
<code>quaternion_slerp(quat0, quat1, fraction[, ...])</code>	Return spherical linear interpolation between two quaternions.
<code>random_quaternion([rand])</code>	Return uniform random unit quaternion.
<code>random_rotation_matrix([rand])</code>	Return uniform random rotation matrix.
<code>random_vector(size)</code>	Return array of random doubles in the half-open interval [0.0, 1.0).
<code>reflection_from_matrix(matrix)</code>	Return mirror plane point and normal vector from reflection matrix.
<code>reflection_matrix(point, normal)</code>	Return matrix to mirror at plane defined by point and normal vector.
<code>rotation_from_matrix(matrix)</code>	Return rotation angle and axis from rotation matrix.
<code>rotation_matrix(angle, direction[, point])</code>	Return matrix to rotate about axis defined by point and direction.
<code>scale_from_matrix(matrix)</code>	Return scaling factor, origin and direction from scaling matrix.
<code>scale_matrix(factor[, origin, direction])</code>	Return matrix to scale by factor around origin in direction.
<code>shear_from_matrix(matrix)</code>	Return shear angle, direction and plane from shear matrix.
<code>shear_matrix(angle, direction, point, normal)</code>	Return matrix to shear by angle along direction vector on shear plane.
<code>superimposition_matrix(v0, v1[, scale, usesvd])</code>	Return matrix to transform given 3D point set into second point set.
<code>translation_from_matrix(matrix)</code>	Return translation vector from translation matrix.
<code>translation_matrix(direction)</code>	Return matrix to translate by direction vector.
<code>unit_vector(data[, axis, out])</code>	Return ndarray normalized by length, i.e. Euclidean norm, along axis.
<code>vector_norm(data[, axis, out])</code>	Return length, i.e. Euclidean norm, of ndarray along axis.
<code>vector_product(v0, v1[, axis])</code>	Return vector perpendicular to vectors.

### 4.2.5 Arcball

**class** transforms3d.\_gohlketransforms.**Arcball**(*initial=None*)

Bases: object

Virtual Trackball Control.

```
>>> ball = Arcball()
>>> ball = Arcball(initial=np.identity(4))
>>> ball.place([320, 320], 320)
>>> ball.down([500, 250])
>>> ball.drag([475, 275])
>>> R = ball.matrix()
>>> numpy.allclose(numpy.sum(R), 3.90583455)
True
>>> ball = Arcball(initial=[1, 0, 0, 0])
```

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```

>>> ball.place([320, 320], 320)
>>> ball.setaxes([1, 1, 0], [-1, 1, 0])
>>> ball.constrain = True
>>> ball.down([400, 200])
>>> ball.drag([200, 400])
>>> R = ball.matrix()
>>> numpy.allclose(numpy.sum(R), 0.2055924)
True
>>> ball.next()

```

**\_\_init\_\_**(*initial=None*)

Initialize virtual trackball control.

*initial* : quaternion or rotation matrix

**property constrain**

Return state of constrain to axis mode.

**down**(*point*)

Set initial cursor window coordinates and pick constrain-axis.

**drag**(*point*)

Update current cursor window coordinates.

**matrix**()

Return homogeneous rotation matrix.

**next**(*acceleration=0.0*)

Continue rotation in direction of last drag.

**place**(*center, radius*)

Place Arcball, e.g. when window size changes.

**center**

[sequence[2]] Window coordinates of trackball center.

**radius**

[float] Radius of trackball in window coordinates.

**setaxes**(\**axes*)

Set axes to constrain rotations.

## 4.2.6 affine\_matrix\_from\_points

`transforms3d._gohlketransforms.affine_matrix_from_points(v0, v1, shear=True, scale=True, usesvd=True)`

Return affine transform matrix to register two point sets.

*v0* and *v1* are shape (ndims, \*) arrays of at least ndims non-homogeneous coordinates, where ndims is the dimensionality of the coordinate space.

If *shear* is False, a similarity transformation matrix is returned. If also *scale* is False, a rigid/Euclidean transformation matrix is returned.

By default the algorithm by Hartley and Zissermann [15] is used. If *usesvd* is True, similarity and Euclidean transformation matrices are calculated by minimizing the weighted sum of squared deviations (RMSD) according



to the algorithm by Kabsch [8]. Otherwise, and if ndims is 3, the quaternion based algorithm by Horn [9] is used, which is slower when using this Python implementation.

The returned matrix performs rotation, translation and uniform scaling (if specified).

```
>>> v0 = [[0, 1031, 1031, 0], [0, 0, 1600, 1600]]
>>> v1 = [[675, 826, 826, 677], [55, 52, 281, 277]]
>>> affine_matrix_from_points(v0, v1)
array([[ 0.14549,  0.00062, 675.50008],
       [ 0.00048,  0.14094, 53.24971],
       [ 0.      ,  0.      ,  1.      ]])
>>> T = translation_matrix(numpy.random.random(3)-0.5)
>>> R = random_rotation_matrix(numpy.random.random(3))
>>> S = scale_matrix(random.random())
>>> M = concatenate_matrices(T, R, S)
>>> v0 = (numpy.random.rand(4, 100) - 0.5) * 20
>>> v0[3] = 1
>>> v1 = numpy.dot(M, v0)
>>> v0[:3] += numpy.random.normal(0, 1e-8, 300).reshape(3, -1)
>>> M = affine_matrix_from_points(v0[:3], v1[:3])
>>> numpy.allclose(v1, numpy.dot(M, v0))
True
```

More examples in `superimposition_matrix()`

## 4.2.7 angle\_between\_vectors

`transforms3d._gohlketransforms.angle_between_vectors(v0, v1, directed=True, axis=0)`

Return angle between vectors.

If directed is False, the input vectors are interpreted as undirected axes, i.e. the maximum angle is  $\pi/2$ .

```
>>> a = angle_between_vectors([1, -2, 3], [-1, 2, -3])
>>> numpy.allclose(a, math.pi)
True
>>> a = angle_between_vectors([1, -2, 3], [-1, 2, -3], directed=False)
>>> numpy.allclose(a, 0)
True
>>> v0 = [[2, 0, 0, 2], [0, 2, 0, 2], [0, 0, 2, 2]]
>>> v1 = [[3], [0], [0]]
>>> a = angle_between_vectors(v0, v1)
>>> numpy.allclose(a, [0, 1.5708, 1.5708, 0.95532])
True
>>> v0 = [[2, 0, 0], [2, 0, 0], [0, 2, 0], [2, 0, 0]]
>>> v1 = [[0, 3, 0], [0, 0, 3], [0, 0, 3], [3, 3, 3]]
>>> a = angle_between_vectors(v0, v1, axis=1)
>>> numpy.allclose(a, [1.5708, 1.5708, 1.5708, 0.95532])
True
```

## 4.2.8 arcball\_constrain\_to\_axis

`transforms3d._gohlketransforms.arcball_constrain_to_axis(point, axis)`

Return sphere point perpendicular to axis.

### 4.2.9 arcball\_map\_to\_sphere

`transforms3d._gohlketransforms.arcball_map_to_sphere(point, center, radius)`

Return unit sphere coordinates from window coordinates.

### 4.2.10 arcball\_nearest\_axis

`transforms3d._gohlketransforms.arcball_nearest_axis(point, axes)`

Return axis, which arc is nearest to point.

### 4.2.11 clip\_matrix

`transforms3d._gohlketransforms.clip_matrix(left, right, bottom, top, near, far, perspective=False)`

Return matrix to obtain normalized device coordinates from frustum.

The frustum bounds are axis-aligned along x (left, right), y (bottom, top) and z (near, far).

Normalized device coordinates are in range [-1, 1] if coordinates are inside the frustum.

If perspective is True the frustum is a truncated pyramid with the perspective point at origin and direction along z axis, otherwise an orthographic canonical view volume (a box).

Homogeneous coordinates transformed by the perspective clip matrix need to be dehomogenized (divided by w coordinate).

```
>>> frustum = numpy.random.rand(6)
>>> frustum[1] += frustum[0]
>>> frustum[3] += frustum[2]
>>> frustum[5] += frustum[4]
>>> M = clip_matrix(perspective=False, *frustum)
>>> numpy.dot(M, [frustum[0], frustum[2], frustum[4], 1])
array([-1., -1., -1.,  1.])
>>> numpy.dot(M, [frustum[1], frustum[3], frustum[5], 1])
array([ 1.,  1.,  1.,  1.])
>>> M = clip_matrix(perspective=True, *frustum)
>>> v = numpy.dot(M, [frustum[0], frustum[2], frustum[4], 1])
>>> v / v[3]
array([-1., -1., -1.,  1.])
>>> v = numpy.dot(M, [frustum[1], frustum[3], frustum[4], 1])
>>> v / v[3]
array([ 1.,  1., -1.,  1.])
```

### 4.2.12 compose\_matrix

`transforms3d._gohlketransforms.compose_matrix(scale=None, shear=None, angles=None,
 translate=None, perspective=None)`

Return transformation matrix from sequence of transformations.

This is the inverse of the `decompose_matrix` function.

**Sequence of transformations:**

scale : vector of 3 scaling factors shear : list of shear factors for x-y, x-z, y-z axes angles : list of Euler angles about static x, y, z axes translate : translation vector along x, y, z axes perspective : perspective partition of matrix

```

>>> scale = numpy.random.random(3) - 0.5
>>> shear = numpy.random.random(3) - 0.5
>>> angles = (numpy.random.random(3) - 0.5) * (2*math.pi)
>>> trans = numpy.random.random(3) - 0.5
>>> persp = numpy.random.random(4) - 0.5
>>> M0 = compose_matrix(scale, shear, angles, trans, persp)
>>> result = decompose_matrix(M0)
>>> M1 = compose_matrix(*result)
>>> is_same_transform(M0, M1)
True

```

### 4.2.13 concatenate\_matrices

`transforms3d._gohlketransforms.concatenate_matrices(*matrices)`

Return concatenation of series of transformation matrices.

```

>>> M = numpy.random.rand(16).reshape((4, 4)) - 0.5
>>> numpy.allclose(M, concatenate_matrices(M))
True
>>> numpy.allclose(numpy.dot(M, M.T), concatenate_matrices(M, M.T))
True

```

### 4.2.14 decompose\_matrix

`transforms3d._gohlketransforms.decompose_matrix(matrix)`

Return sequence of transformations from transformation matrix.

**matrix**

[array\_like] Non-degenerative homogeneous transformation matrix

**Return tuple of:**

scale : vector of 3 scaling factors shear : list of shear factors for x-y, x-z, y-z axes angles : list of Euler angles about static x, y, z axes translate : translation vector along x, y, z axes perspective : perspective partition of matrix

Raise ValueError if matrix is of wrong type or degenerative.

```

>>> T0 = translation_matrix([1, 2, 3])
>>> scale, shear, angles, trans, persp = decompose_matrix(T0)
>>> T1 = translation_matrix(trans)
>>> numpy.allclose(T0, T1)
True
>>> S = scale_matrix(0.123)
>>> scale, shear, angles, trans, persp = decompose_matrix(S)
>>> scale[0]
0.123
>>> R0 = euler_matrix(1, 2, 3)
>>> scale, shear, angles, trans, persp = decompose_matrix(R0)
>>> R1 = euler_matrix(*angles)
>>> numpy.allclose(R0, R1)
True

```

### 4.2.15 euler\_from\_matrix

`transforms3d._gohlketransforms.euler_from_matrix(matrix, axes='sxyz')`

Return Euler angles from rotation matrix for specified axis sequence.

axes : One of 24 axis sequences as string or encoded tuple

Note that many Euler angle triplets can describe one matrix.

```
>>> R0 = euler_matrix(1, 2, 3, 'syxz')
>>> al, be, ga = euler_from_matrix(R0, 'syxz')
>>> R1 = euler_matrix(al, be, ga, 'syxz')
>>> numpy.allclose(R0, R1)
True
>>> angles = (4*math.pi) * (numpy.random.random(3) - 0.5)
>>> for axes in _AXES2TUPLE.keys():
...     R0 = euler_matrix(axes=axes, *angles)
...     R1 = euler_matrix(axes=axes, *euler_from_matrix(R0, axes))
...     if not numpy.allclose(R0, R1): print(axes, "failed")
```

### 4.2.16 euler\_from\_quaternion

`transforms3d._gohlketransforms.euler_from_quaternion(quaternion, axes='sxyz')`

Return Euler angles from quaternion for specified axis sequence.

```
>>> angles = euler_from_quaternion([0.99810947, 0.06146124, 0, 0])
>>> numpy.allclose(angles, [0.123, 0, 0])
True
```

### 4.2.17 euler\_matrix

`transforms3d._gohlketransforms.euler_matrix(ai, aj, ak, axes='sxyz')`

Return homogeneous rotation matrix from Euler angles and axis sequence.

ai, aj, ak : Euler's roll, pitch and yaw angles axes : One of 24 axis sequences as string or encoded tuple

```
>>> R = euler_matrix(1, 2, 3, 'syxz')
>>> numpy.allclose(numpy.sum(R[0]), -1.34786452)
True
>>> R = euler_matrix(1, 2, 3, (0, 1, 0, 1))
>>> numpy.allclose(numpy.sum(R[0]), -0.383436184)
True
>>> ai, aj, ak = (4*math.pi) * (numpy.random.random(3) - 0.5)
>>> for axes in _AXES2TUPLE.keys():
...     R = euler_matrix(ai, aj, ak, axes)
>>> for axes in _TUPLE2AXES.keys():
...     R = euler_matrix(ai, aj, ak, axes)
```

### 4.2.18 identity\_matrix

`transforms3d._gohlketransforms.identity_matrix()`

Return 4x4 identity/unit matrix.

```
>>> I = identity_matrix()
>>> numpy.allclose(I, numpy.dot(I, I))
True
>>> numpy.sum(I), numpy.trace(I)
(4.0, 4.0)
>>> numpy.allclose(I, numpy.identity(4))
True
```

#### 4.2.19 inverse\_matrix

`transforms3d._gohlketransforms.inverse_matrix(matrix)`

Return inverse of square transformation matrix.

```
>>> M0 = random_rotation_matrix()
>>> M1 = inverse_matrix(M0.T)
>>> numpy.allclose(M1, numpy.linalg.inv(M0.T))
True
>>> for size in range(1, 7):
...     M0 = numpy.random.rand(size, size)
...     M1 = inverse_matrix(M0)
...     if not numpy.allclose(M1, numpy.linalg.inv(M0)): print(size)
```

#### 4.2.20 is\_same\_quaternion

`transforms3d._gohlketransforms.is_same_quaternion(q0, q1)`

Return True if two quaternions are equal.

#### 4.2.21 is\_same\_transform

`transforms3d._gohlketransforms.is_same_transform(matrix0, matrix1)`

Return True if two matrices perform same transformation.

```
>>> is_same_transform(numpy.identity(4), numpy.identity(4))
True
>>> is_same_transform(numpy.identity(4), random_rotation_matrix())
False
```

#### 4.2.22 orthogonalization\_matrix

`transforms3d._gohlketransforms.orthogonalization_matrix(lengths, angles)`

Return orthogonalization matrix for crystallographic cell coordinates.

Angles are expected in degrees.

The de-orthogonalization matrix is the inverse.

```
>>> O = orthogonalization_matrix([10, 10, 10], [90, 90, 90])
>>> numpy.allclose(O[:3, :3], numpy.identity(3, float) * 10)
True
>>> O = orthogonalization_matrix([9.8, 12.0, 15.5], [87.2, 80.7, 69.7])
>>> numpy.allclose(numpy.sum(O), 43.063229)
True
```

### 4.2.23 projection\_from\_matrix

`transforms3d._gohlketransforms.projection_from_matrix(matrix, pseudo=False)`

Return projection plane and perspective point from projection matrix.

Return values are same as arguments for `projection_matrix` function: `point`, `normal`, `direction`, `perspective`, and `pseudo`.

```
>>> point = numpy.random.random(3) - 0.5
>>> normal = numpy.random.random(3) - 0.5
>>> direct = numpy.random.random(3) - 0.5
>>> persp = numpy.random.random(3) - 0.5
>>> P0 = projection_matrix(point, normal)
>>> result = projection_from_matrix(P0)
>>> P1 = projection_matrix(*result)
>>> is_same_transform(P0, P1)
True
>>> P0 = projection_matrix(point, normal, direct)
>>> result = projection_from_matrix(P0)
>>> P1 = projection_matrix(*result)
>>> is_same_transform(P0, P1)
True
>>> P0 = projection_matrix(point, normal, perspective=persp, pseudo=False)
>>> result = projection_from_matrix(P0, pseudo=False)
>>> P1 = projection_matrix(*result)
>>> is_same_transform(P0, P1)
True
>>> P0 = projection_matrix(point, normal, perspective=persp, pseudo=True)
>>> result = projection_from_matrix(P0, pseudo=True)
>>> P1 = projection_matrix(*result)
>>> is_same_transform(P0, P1)
True
```

### 4.2.24 projection\_matrix

`transforms3d._gohlketransforms.projection_matrix(point, normal, direction=None, perspective=None, pseudo=False)`

Return matrix to project onto plane defined by point and normal.

Using either perspective point, projection direction, or none of both.

If `pseudo` is `True`, perspective projections will preserve relative depth such that `Perspective = dot(Orthogonal, PseudoPerspective)`.

```
>>> P = projection_matrix([0, 0, 0], [1, 0, 0])
>>> numpy.allclose(P[1:, 1:], numpy.identity(4)[1:, 1:])
True
>>> point = numpy.random.random(3) - 0.5
>>> normal = numpy.random.random(3) - 0.5
>>> direct = numpy.random.random(3) - 0.5
>>> persp = numpy.random.random(3) - 0.5
>>> P0 = projection_matrix(point, normal)
>>> P1 = projection_matrix(point, normal, direction=direct)
>>> P2 = projection_matrix(point, normal, perspective=persp)
```

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```

>>> P3 = projection_matrix(point, normal, perspective=persp, pseudo=True)
>>> is_same_transform(P2, numpy.dot(P0, P3))
True
>>> P = projection_matrix([3, 0, 0], [1, 1, 0], [1, 0, 0])
>>> v0 = (numpy.random.rand(4, 5) - 0.5) * 20
>>> v0[3] = 1
>>> v1 = numpy.dot(P, v0)
>>> numpy.allclose(v1[1], v0[1])
True
>>> numpy.allclose(v1[0], 3-v1[1])
True

```

#### 4.2.25 quaternion\_about\_axis

`transforms3d._gohlketransforms.quaternion_about_axis(angle, axis)`

Return quaternion for rotation about axis.

```

>>> q = quaternion_about_axis(0.123, [1, 0, 0])
>>> numpy.allclose(q, [0.99810947, 0.06146124, 0, 0])
True

```

#### 4.2.26 quaternion\_conjugate

`transforms3d._gohlketransforms.quaternion_conjugate(quaternion)`

Return conjugate of quaternion.

```

>>> q0 = random_quaternion()
>>> q1 = quaternion_conjugate(q0)
>>> q1[0] == q0[0] and all(q1[1:] == -q0[1:])
True

```

#### 4.2.27 quaternion\_from\_euler

`transforms3d._gohlketransforms.quaternion_from_euler(ai, aj, ak, axes='sxyz')`

Return quaternion from Euler angles and axis sequence.

*ai*, *aj*, *ak* : Euler's roll, pitch and yaw angles *axes* : One of 24 axis sequences as string or encoded tuple

```

>>> q = quaternion_from_euler(1, 2, 3, 'ryxz')
>>> numpy.allclose(q, [0.435953, 0.310622, -0.718287, 0.444435])
True

```

#### 4.2.28 quaternion\_from\_matrix

`transforms3d._gohlketransforms.quaternion_from_matrix(matrix, isprecise=False)`

Return quaternion from rotation matrix.

If *isprecise* is True, the input matrix is assumed to be a precise rotation matrix and a faster algorithm is used.

```

>>> q = quaternion_from_matrix(numpy.identity(4), True)
>>> numpy.allclose(q, [1, 0, 0, 0])
True
>>> q = quaternion_from_matrix(numpy.diag([1, -1, -1, 1]))
>>> numpy.allclose(q, [0, 1, 0, 0]) or numpy.allclose(q, [0, -1, 0, 0])
True
>>> R = rotation_matrix(0.123, (1, 2, 3))
>>> q = quaternion_from_matrix(R, True)
>>> numpy.allclose(q, [0.9981095, 0.0164262, 0.0328524, 0.0492786])
True
>>> R = [[-0.545, 0.797, 0.260, 0], [0.733, 0.603, -0.313, 0],
...      [-0.407, 0.021, -0.913, 0], [0, 0, 0, 1]]
>>> q = quaternion_from_matrix(R)
>>> numpy.allclose(q, [0.19069, 0.43736, 0.87485, -0.083611])
True
>>> R = [[0.395, 0.362, 0.843, 0], [-0.626, 0.796, -0.056, 0],
...      [-0.677, -0.498, 0.529, 0], [0, 0, 0, 1]]
>>> q = quaternion_from_matrix(R)
>>> numpy.allclose(q, [0.82336615, -0.13610694, 0.46344705, -0.29792603])
True
>>> R = random_rotation_matrix()
>>> q = quaternion_from_matrix(R)
>>> is_same_transform(R, quaternion_matrix(q))
True
>>> is_same_quaternion(quaternion_from_matrix(R, isprecise=False),
...                    quaternion_from_matrix(R, isprecise=True))
True
>>> R = euler_matrix(0.0, 0.0, numpy.pi/2.0)
>>> is_same_quaternion(quaternion_from_matrix(R, isprecise=False),
...                    quaternion_from_matrix(R, isprecise=True))
True

```

### 4.2.29 quaternion\_imag

`transforms3d._gohlketransforms.quaternion_imag(quaternion)`

Return imaginary part of quaternion.

```

>>> quaternion_imag([3, 0, 1, 2])
array([ 0.,  1.,  2.])

```

### 4.2.30 quaternion\_inverse

`transforms3d._gohlketransforms.quaternion_inverse(quaternion)`

Return inverse of quaternion.

```

>>> q0 = random_quaternion()
>>> q1 = quaternion_inverse(q0)
>>> numpy.allclose(quaternion_multiply(q0, q1), [1, 0, 0, 0])
True

```



### 4.2.31 quaternion\_matrix

`transforms3d._gohlketransforms.quaternion_matrix(Quaternion)`

Return homogeneous rotation matrix from quaternion.

```
>>> M = quaternion_matrix([0.99810947, 0.06146124, 0, 0])
>>> numpy.allclose(M, rotation_matrix(0.123, [1, 0, 0]))
True
>>> M = quaternion_matrix([1, 0, 0, 0])
>>> numpy.allclose(M, numpy.identity(4))
True
>>> M = quaternion_matrix([0, 1, 0, 0])
>>> numpy.allclose(M, numpy.diag([1, -1, -1, 1]))
True
```

### 4.2.32 quaternion\_multiply

`transforms3d._gohlketransforms.quaternion_multiply(Quaternion1, Quaternion0)`

Return multiplication of two quaternions.

```
>>> q = quaternion_multiply([4, 1, -2, 3], [8, -5, 6, 7])
>>> numpy.allclose(q, [28, -44, -14, 48])
True
```

### 4.2.33 quaternion\_real

`transforms3d._gohlketransforms.quaternion_real(Quaternion)`

Return real part of quaternion.

```
>>> quaternion_real([3, 0, 1, 2])
3.0
```

### 4.2.34 quaternion\_slerp

`transforms3d._gohlketransforms.quaternion_slerp(Quaternion0, Quaternion1, fraction, spin=0, shortestpath=True)`

Return spherical linear interpolation between two quaternions.

```
>>> q0 = random_quaternion()
>>> q1 = random_quaternion()
>>> q = quaternion_slerp(q0, q1, 0)
>>> numpy.allclose(q, q0)
True
>>> q = quaternion_slerp(q0, q1, 1, 1)
>>> numpy.allclose(q, q1)
True
>>> q = quaternion_slerp(q0, q1, 0.5)
>>> angle = math.acos(numpy.dot(q0, q1))
>>> numpy.allclose(2, math.acos(numpy.dot(q0, q1)) / angle) or numpy.
    ↳ allclose(2, math.acos(-numpy.dot(q0, q1)) / angle)
True
```

### 4.2.35 random\_quaternion

`transforms3d._gohlketransforms.random_quaternion(rand=None)`

Return uniform random unit quaternion.

**rand:** array like or None

Three independent random variables that are uniformly distributed between 0 and 1.

```
>>> q = random_quaternion()
>>> numpy.allclose(1, vector_norm(q))
True
>>> q = random_quaternion(numpy.random.random(3))
>>> len(q.shape), q.shape[0]==4
(1, True)
```

### 4.2.36 random\_rotation\_matrix

`transforms3d._gohlketransforms.random_rotation_matrix(rand=None)`

Return uniform random rotation matrix.

**rand:** array like

Three independent random variables that are uniformly distributed between 0 and 1 for each returned quaternion.

```
>>> R = random_rotation_matrix()
>>> numpy.allclose(numpy.dot(R.T, R), numpy.identity(4))
True
```

### 4.2.37 random\_vector

`transforms3d._gohlketransforms.random_vector(size)`

Return array of random doubles in the half-open interval [0.0, 1.0).

```
>>> v = random_vector(10000)
>>> numpy.all(v >= 0) and numpy.all(v < 1)
True
>>> v0 = random_vector(10)
>>> v1 = random_vector(10)
>>> numpy.any(v0 == v1)
False
```

### 4.2.38 reflection\_from\_matrix

`transforms3d._gohlketransforms.reflection_from_matrix(matrix)`

Return mirror plane point and normal vector from reflection matrix.

```
>>> v0 = numpy.random.random(3) - 0.5
>>> v1 = numpy.random.random(3) - 0.5
>>> M0 = reflection_matrix(v0, v1)
>>> point, normal = reflection_from_matrix(M0)
>>> M1 = reflection_matrix(point, normal)
>>> is_same_transform(M0, M1)
True
```

### 4.2.39 reflection\_matrix

`transforms3d._gohlketransforms.reflection_matrix(point, normal)`

Return matrix to mirror at plane defined by point and normal vector.

```
>>> v0 = numpy.random.random(4) - 0.5
>>> v0[3] = 1.
>>> v1 = numpy.random.random(3) - 0.5
>>> R = reflection_matrix(v0, v1)
>>> numpy.allclose(2, numpy.trace(R))
True
>>> numpy.allclose(v0, numpy.dot(R, v0))
True
>>> v2 = v0.copy()
>>> v2[:3] += v1
>>> v3 = v0.copy()
>>> v2[:3] -= v1
>>> numpy.allclose(v2, numpy.dot(R, v3))
True
```

### 4.2.40 rotation\_from\_matrix

`transforms3d._gohlketransforms.rotation_from_matrix(matrix)`

Return rotation angle and axis from rotation matrix.

```
>>> angle = (random.random() - 0.5) * (2*math.pi)
>>> direc = numpy.random.random(3) - 0.5
>>> point = numpy.random.random(3) - 0.5
>>> R0 = rotation_matrix(angle, direc, point)
>>> angle, direc, point = rotation_from_matrix(R0)
>>> R1 = rotation_matrix(angle, direc, point)
>>> is_same_transform(R0, R1)
True
```

### 4.2.41 rotation\_matrix

`transforms3d._gohlketransforms.rotation_matrix(angle, direction, point=None)`

Return matrix to rotate about axis defined by point and direction.

```
>>> R = rotation_matrix(math.pi/2, [0, 0, 1], [1, 0, 0])
>>> numpy.allclose(numpy.dot(R, [0, 0, 0, 1]), [1, -1, 0, 1])
True
>>> angle = (random.random() - 0.5) * (2*math.pi)
>>> direc = numpy.random.random(3) - 0.5
>>> point = numpy.random.random(3) - 0.5
>>> R0 = rotation_matrix(angle, direc, point)
>>> R1 = rotation_matrix(angle-2*math.pi, direc, point)
>>> is_same_transform(R0, R1)
True
>>> R0 = rotation_matrix(angle, direc, point)
>>> R1 = rotation_matrix(-angle, -direc, point)
>>> is_same_transform(R0, R1)
```

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```

True
>>> I = numpy.identity(4, numpy.float64)
>>> numpy.allclose(I, rotation_matrix(math.pi*2, direc))
True
>>> numpy.allclose(2, numpy.trace(rotation_matrix(math.pi/2,
...                                              direc, point)))
True

```

#### 4.2.42 scale\_from\_matrix

`transforms3d._gohlketransforms.scale_from_matrix(matrix)`

Return scaling factor, origin and direction from scaling matrix.

```

>>> factor = random.random() * 10 - 5
>>> origin = numpy.random.random(3) - 0.5
>>> direct = numpy.random.random(3) - 0.5
>>> S0 = scale_matrix(factor, origin)
>>> factor, origin, direction = scale_from_matrix(S0)
>>> S1 = scale_matrix(factor, origin, direction)
>>> is_same_transform(S0, S1)
True
>>> S0 = scale_matrix(factor, origin, direct)
>>> factor, origin, direction = scale_from_matrix(S0)
>>> S1 = scale_matrix(factor, origin, direction)
>>> is_same_transform(S0, S1)
True

```

#### 4.2.43 scale\_matrix

`transforms3d._gohlketransforms.scale_matrix(factor, origin=None, direction=None)`

Return matrix to scale by factor around origin in direction.

Use factor -1 for point symmetry.

```

>>> v = (numpy.random.rand(4, 5) - 0.5) * 20
>>> v[3] = 1
>>> S = scale_matrix(-1.234)
>>> numpy.allclose(numpy.dot(S, v)[:3], -1.234*v[:3])
True
>>> factor = random.random() * 10 - 5
>>> origin = numpy.random.random(3) - 0.5
>>> direct = numpy.random.random(3) - 0.5
>>> S = scale_matrix(factor, origin)
>>> S = scale_matrix(factor, origin, direct)

```

#### 4.2.44 shear\_from\_matrix

`transforms3d._gohlketransforms.shear_from_matrix(matrix)`

Return shear angle, direction and plane from shear matrix.

```

>>> angle = (random.random() - 0.5) * 4*math.pi
>>> direct = numpy.random.random(3) - 0.5
>>> point = numpy.random.random(3) - 0.5
>>> normal = numpy.cross(direct, numpy.random.random(3))
>>> S0 = shear_matrix(angle, direct, point, normal)
>>> angle, direct, point, normal = shear_from_matrix(S0)
>>> S1 = shear_matrix(angle, direct, point, normal)
>>> is_same_transform(S0, S1)
True

```

#### 4.2.45 shear\_matrix

`transforms3d._gohlketransforms.shear_matrix(angle, direction, point, normal)`

Return matrix to shear by angle along direction vector on shear plane.

The shear plane is defined by a point and normal vector. The direction vector must be orthogonal to the plane's normal vector.

A point P is transformed by the shear matrix into P'' such that the vector P-P'' is parallel to the direction vector and its extent is given by the angle of P-P'-P'', where P' is the orthogonal projection of P onto the shear plane.

```

>>> angle = (random.random() - 0.5) * 4*math.pi
>>> direct = numpy.random.random(3) - 0.5
>>> point = numpy.random.random(3) - 0.5
>>> normal = numpy.cross(direct, numpy.random.random(3))
>>> S = shear_matrix(angle, direct, point, normal)
>>> numpy.allclose(1, numpy.linalg.det(S))
True

```

#### 4.2.46 superimposition\_matrix

`transforms3d._gohlketransforms.superimposition_matrix(v0, v1, scale=False, usesvd=True)`

Return matrix to transform given 3D point set into second point set.

*v0* and *v1* are shape (3, \*) or (4, \*) arrays of at least 3 points.

The parameters *scale* and *usesvd* are explained in the more general `affine_matrix_from_points` function.

The returned matrix is a similarity or Euclidean transformation matrix. This function has a fast C implementation in `transformations.c`.

```

>>> v0 = numpy.random.rand(3, 10)
>>> M = superimposition_matrix(v0, v0)
>>> numpy.allclose(M, numpy.identity(4))
True
>>> R = random_rotation_matrix(numpy.random.random(3))
>>> v0 = [[1,0,0], [0,1,0], [0,0,1], [1,1,1]]
>>> v1 = numpy.dot(R, v0)
>>> M = superimposition_matrix(v0, v1)
>>> numpy.allclose(v1, numpy.dot(M, v0))
True
>>> v0 = (numpy.random.rand(4, 100) - 0.5) * 20
>>> v0[3] = 1
>>> v1 = numpy.dot(R, v0)

```

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```

>>> M = superimposition_matrix(v0, v1)
>>> numpy.allclose(v1, numpy.dot(M, v0))
True
>>> S = scale_matrix(random.random())
>>> T = translation_matrix(numpy.random.random(3)-0.5)
>>> M = concatenate_matrices(T, R, S)
>>> v1 = numpy.dot(M, v0)
>>> v0[:3] += numpy.random.normal(0, 1e-9, 300).reshape(3, -1)
>>> M = superimposition_matrix(v0, v1, scale=True)
>>> numpy.allclose(v1, numpy.dot(M, v0))
True
>>> M = superimposition_matrix(v0, v1, scale=True, usesvd=False)
>>> numpy.allclose(v1, numpy.dot(M, v0))
True
>>> v = numpy.empty((4, 100, 3))
>>> v[:, :, 0] = v0
>>> M = superimposition_matrix(v0, v1, scale=True, usesvd=False)
>>> numpy.allclose(v1, numpy.dot(M, v[:, :, 0]))
True

```

#### 4.2.47 translation\_from\_matrix

`transforms3d._gohlketransforms.translation_from_matrix(matrix)`

Return translation vector from translation matrix.

```

>>> v0 = numpy.random.random(3) - 0.5
>>> v1 = translation_from_matrix(translation_matrix(v0))
>>> numpy.allclose(v0, v1)
True

```

#### 4.2.48 translation\_matrix

`transforms3d._gohlketransforms.translation_matrix(direction)`

Return matrix to translate by direction vector.

```

>>> v = numpy.random.random(3) - 0.5
>>> numpy.allclose(v, translation_matrix(v)[:3, 3])
True

```

#### 4.2.49 unit\_vector

`transforms3d._gohlketransforms.unit_vector(data, axis=None, out=None)`

Return ndarray normalized by length, i.e. Euclidean norm, along axis.

```

>>> v0 = numpy.random.random(3)
>>> v1 = unit_vector(v0)
>>> numpy.allclose(v1, v0 / numpy.linalg.norm(v0))
True
>>> v0 = numpy.random.rand(5, 4, 3)
>>> v1 = unit_vector(v0, axis=-1)

```

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```

>>> v2 = v0 / numpy.expand_dims(numpy.sqrt(numpy.sum(v0*v0, axis=2)), 2)
>>> numpy.allclose(v1, v2)
True
>>> v1 = unit_vector(v0, axis=1)
>>> v2 = v0 / numpy.expand_dims(numpy.sqrt(numpy.sum(v0*v0, axis=1)), 1)
>>> numpy.allclose(v1, v2)
True
>>> v1 = numpy.empty((5, 4, 3))
>>> unit_vector(v0, axis=1, out=v1)
>>> numpy.allclose(v1, v2)
True
>>> list(unit_vector([]))
[]
>>> list(unit_vector([1]))
[1.0]

```

### 4.2.50 vector\_norm

transforms3d.\_gohlketransforms.**vector\_norm**(data, axis=None, out=None)

Return length, i.e. Euclidean norm, of ndarray along axis.

```

>>> v = numpy.random.random(3)
>>> n = vector_norm(v)
>>> numpy.allclose(n, numpy.linalg.norm(v))
True
>>> v = numpy.random.rand(6, 5, 3)
>>> n = vector_norm(v, axis=-1)
>>> numpy.allclose(n, numpy.sqrt(numpy.sum(v*v, axis=2)))
True
>>> n = vector_norm(v, axis=1)
>>> numpy.allclose(n, numpy.sqrt(numpy.sum(v*v, axis=1)))
True
>>> v = numpy.random.rand(5, 4, 3)
>>> n = numpy.empty((5, 3))
>>> vector_norm(v, axis=1, out=n)
>>> numpy.allclose(n, numpy.sqrt(numpy.sum(v*v, axis=1)))
True
>>> vector_norm([])
0.0
>>> vector_norm([1])
1.0

```

### 4.2.51 vector\_product

transforms3d.\_gohlketransforms.**vector\_product**(v0, v1, axis=0)

Return vector perpendicular to vectors.

```

>>> v = vector_product([2, 0, 0], [0, 3, 0])
>>> numpy.allclose(v, [0, 0, 6])
True
>>> v0 = [[2, 0, 0, 2], [0, 2, 0, 2], [0, 0, 2, 2]]

```

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```

>>> v1 = [[3], [0], [0]]
>>> v = vector_product(v0, v1)
>>> numpy.allclose(v, [[0, 0, 0, 0], [0, 0, 6, 6], [0, -6, 0, -6]])
True
>>> v0 = [[2, 0, 0], [2, 0, 0], [0, 2, 0], [2, 0, 0]]
>>> v1 = [[0, 3, 0], [0, 0, 3], [0, 0, 3], [3, 3, 3]]
>>> v = vector_product(v0, v1, axis=1)
>>> numpy.allclose(v, [[0, 0, 6], [0, -6, 0], [6, 0, 0], [0, -6, 6]])
True

```

## 4.3 \_version

```
get_versions()
```

### 4.3.1 get\_versions

```
transforms3d._version.get_versions()
```

## 4.4 affines

Compose and decompose homogenous affine - usually 4x4 - matrices

<i>compose</i> (T, R, Z[, S])	Compose translations, rotations, zooms, [shears] to affine
<i>decompose</i> (A)	Decompose homogenous affine transformation matrix A into parts.
<i>decompose44</i> (A44)	Decompose 4x4 homogenous affine matrix into parts.

### 4.4.1 compose

```
transforms3d.affines.compose(T, R, Z, S=None)
```

Compose translations, rotations, zooms, [shears] to affine

#### Parameters

**T**

[array-like shape (N,)] Translations, where N is usually 3 (3D case)

**R**

[array-like shape (N,N)] Rotation matrix where N is usually 3 (3D case)

**Z**

[array-like shape (N,)] Zooms, where N is usually 3 (3D case)

**S**

[array-like, shape (P), optional] Shear vector, such that shears fill upper triangle above diagonal to form shear matrix. P is the (N-2)th Triangular number, which happens to be 3 for a 4x4 affine (3D case)

#### Returns



**A**

[array, shape (N+1, N+1)] Affine transformation matrix where N usually == 3 (3D case)

**Examples**

```

>>> T = [20, 30, 40] # translations
>>> R = [[0, -1, 0], [1, 0, 0], [0, 0, 1]] # rotation matrix
>>> Z = [2.0, 3.0, 4.0] # zooms
>>> A = compose(T, R, Z)
>>> A
array([[ 0., -3.,  0., 20.],
       [ 2.,  0.,  0., 30.],
       [ 0.,  0.,  4., 40.],
       [ 0.,  0.,  0.,  1.]])
>>> S = np.zeros(3)
>>> B = compose(T, R, Z, S)
>>> assert(np.all(A == B)) # True

```

A null set

```

>>> compose(np.zeros(3), np.eye(3), np.ones(3), np.zeros(3))
array([[1., 0., 0., 0.],
       [0., 1., 0., 0.],
       [0., 0., 1., 0.],
       [0., 0., 0., 1.]])

```

**4.4.2 decompose**`transforms3d.affines.decompose(A)`Decompose homogenous affine transformation matrix *A* into parts.

The parts are translations, rotations, zooms, shears.

*A* can be any square matrix, but is typically shape (4,4).Decomposes *A* into *T*, *R*, *Z*, *S*, such that, if *A* is shape (4,4):

```

Smat = np.array([[1, S[0], S[1]],
                 [0,  1, S[2]],
                 [0,  0,  1]])
RZS = np.dot(R, np.dot(np.diag(Z), Smat))
A = np.eye(4)
A[:3, :3] = RZS
A[-1, -1] = T

```

The order of transformations is therefore shears, followed by zooms, followed by rotations, followed by translations.

The case above (*A*.shape == (4,4)) is the most common, and corresponds to a 3D affine, but in fact *A* need only be square.**Parameters****A**

[array shape (N,N)]

**Returns**

<b>T</b>	[array, shape (N-1,)] Translation vector
<b>R</b>	[array shape (N-1, N-1)] rotation matrix
<b>Z</b>	[array, shape (N-1,)] Zoom vector. May have one negative zoom to prevent need for negative determinant R matrix above
<b>S</b>	[array, shape (P,)] Shear vector, such that shears fill upper triangle above diagonal to form shear matrix. P is the (N-2)th Triangular number, which happens to be 3 for a 4x4 affine.

### Notes

We have used a nice trick from SPM to get the shears. Let us call the starting N-1 by N-1 matrix RZS, because it is the composition of the rotations on the zooms on the shears. The rotation matrix R must have the property `np.dot(R.T, R) == np.eye(N-1)`. Thus `np.dot(RZS.T, RZS)` will, by the transpose rules, be equal to `np.dot((ZS).T, (ZS))`. Because we are doing shears with the upper right part of the matrix, that means that the Cholesky decomposition of `np.dot(RZS.T, RZS)` will give us our ZS matrix, from which we take the zooms from the diagonal, and the shear values from the off-diagonal elements.

### Examples

```
>>> T = [20, 30, 40] # translations
>>> R = [[0, -1, 0], [1, 0, 0], [0, 0, 1]] # rotation matrix
>>> Z = [2.0, 3.0, 4.0] # zooms
>>> S = [0.2, 0.1, 0.3] # shears
>>> # Now we make an affine matrix
>>> A = np.eye(4)
>>> Smat = np.array([[1, S[0], S[1]],
...                  [0, 1, S[2]],
...                  [0, 0, 1]])
>>> RZS = np.dot(R, np.dot(np.diag(Z), Smat))
>>> A[:3,:3] = RZS
>>> A[:-1,-1] = T # set translations
>>> Tdash, Rdash, Zdash, Sdash = decompose(A)
>>> np.allclose(T, Tdash)
True
>>> np.allclose(R, Rdash)
True
>>> np.allclose(Z, Zdash)
True
>>> np.allclose(S, Sdash)
True
```

### 4.4.3 decompose44

`transforms3d.affines.decompose44(A44)`

Decompose 4x4 homogenous affine matrix into parts.

The parts are translations, rotations, zooms, shears.

This is the same as `decompose()` but specialized for 4x4 affines.

Decomposes *A44* into T, R, Z, S, such that:

```

Smat = np.array([[1, S[0], S[1]],
                 [0, 1, S[2]],
                 [0, 0, 1]])
RZS = np.dot(R, np.dot(np.diag(Z), Smat))
A44 = np.eye(4)
A44[:3,:3] = RZS
A44[:,-1] = T

```

The order of transformations is therefore shears, followed by zooms, followed by rotations, followed by translations.

This routine only works for shape (4,4) matrices

#### Parameters

##### A44

[array shape (4,4)]

#### Returns

##### T

[array, shape (3,)] Translation vector

##### R

[array shape (3,3)] rotation matrix

##### Z

[array, shape (3,)] Zoom vector. May have one negative zoom to prevent need for negative determinant R matrix above

##### S

[array, shape (3,)] Shear vector, such that shears fill upper triangle above diagonal to form shear matrix (type `striu`).

#### Notes

The implementation inspired by:

*Decomposing a matrix into simple transformations* by Spencer W. Thomas, pp 320-323 in *Graphics Gems II*, James Arvo (editor), Academic Press, 1991, ISBN: 0120644819.

The upper left 3x3 of the affine consists of a matrix we'll call RZS:

```
RZS = R * Z * S
```

where R is a rotation matrix, Z is a diagonal matrix of scalings:

```
Z = diag([sx, sy, sz])
```

and S is a shear matrix of form:

```

S = [[1, sxy, sxz],
     [0, 1, syz],
     [0, 0, 1]]

```

Running all this through sympy (see 'derivations' folder) gives RZS as

```
[R00*sx, R01*sy + R00*sx*sxy, R02*sz + R00*sx*sxz + R01*sy*syz]
[R10*sx, R11*sy + R10*sx*sxy, R12*sz + R10*sx*sxz + R11*sy*syz]
[R20*sx, R21*sy + R20*sx*sxy, R22*sz + R20*sx*sxz + R21*sy*syz]
```

R is defined as being a rotation matrix, so the dot products between the columns of R are zero, and the norm of each column is 1. Thus the dot product:

```
R[:,0].T * RZS[:,1]
```

that results in:

```
[R00*R01*sy + R10*R11*sy + R20*R21*sy + sx*sxy*R00**2 + sx*sxy*R10**2 +
↪sx*sxy*R20**2]
```

simplifies to  $sy*0 + sx*sxy*1 == sx*sxy$ . Therefore:

```
R[:,1] * sy = RZS[:,1] - R[:,0] * (R[:,0].T * RZS[:,1])
```

allowing us to get sy with the norm, and sxy with  $R[:,0].T * RZS[:,1] / sx$ .

Similarly  $R[:,0].T * RZS[:,2]$  simplifies to  $sx*sxz$ , and  $R[:,1].T * RZS[:,2]$  to  $sy*syz$  giving us the remaining unknowns.

## Examples

```
>>> T = [20, 30, 40] # translations
>>> R = [[0, -1, 0], [1, 0, 0], [0, 0, 1]] # rotation matrix
>>> Z = [2.0, 3.0, 4.0] # zooms
>>> S = [0.2, 0.1, 0.3] # shears
>>> # Now we make an affine matrix
>>> A = np.eye(4)
>>> Smat = np.array([[1, S[0], S[1]],
...                  [0, 1, S[2]],
...                  [0, 0, 1]])
>>> RZS = np.dot(R, np.dot(np.diag(Z), Smat))
>>> A[:3,:3] = RZS
>>> A[:,-1] = T # set translations
>>> Tdash, Rdash, Zdash, Sdash = decompose44(A)
>>> np.allclose(T, Tdash)
True
>>> np.allclose(R, Rdash)
True
>>> np.allclose(Z, Zdash)
True
>>> np.allclose(S, Sdash)
True
```

## 4.5 axangles

Functions for working with axis, angle rotations

See [quaternions](#) for conversions between axis, angle pairs and quaternions.

Terms used in function names:

- *mat* : array shape (3, 3) (3D non-homogenous coordinates)
- *aff* : affine array shape (4, 4) (3D homogenous coordinates)
- *axangle* : rotations encoded by axis vector and angle scalar

<code>aff2axangle(aff)</code>	Return axis, angle and point from affine
<code>axangle2aff(axis, angle[, point])</code>	Return affine encoding rotation by <i>angle</i> about <i>axis</i> .
<code>axangle2mat(axis, angle[, is_normalized])</code>	Rotation matrix for rotation angle <i>angle</i> around <i>axis</i>
<code>mat2axangle(mat[, unit_thresh])</code>	Return axis, angle and point from (3, 3) matrix <i>mat</i>

### 4.5.1 aff2axangle

`transforms3d.axangles.aff2axangle(aff)`

Return axis, angle and point from affine

#### Parameters

**aff**

[array-like shape (4,4)]

#### Returns

**axis**

[array shape (3,)] vector giving axis of rotation

**angle**

[scalar] angle of rotation in radians.

**point**

[array shape (3,)] point around which rotation is performed

#### Notes

[http://en.wikipedia.org/wiki/Rotation\\_matrix#Axis\\_of\\_a\\_rotation](http://en.wikipedia.org/wiki/Rotation_matrix#Axis_of_a_rotation)

#### Examples

```
>>> direc = np.random.random(3) - 0.5
>>> angle = (np.random.random() - 0.5) * (2*math.pi)
>>> point = np.random.random(3) - 0.5
>>> R0 = axangle2aff(direc, angle, point)
>>> direc, angle, point = aff2axangle(R0)
>>> R1 = axangle2aff(direc, angle, point)
>>> np.allclose(R0, R1)
True
```

### 4.5.2 axangle2aff

`transforms3d.axangles.axangle2aff(axis, angle, point=None)`

Return affine encoding rotation by *angle* about *axis*.

#### Parameters

**axis**

[array shape (3,)] vector giving axis of rotation

**angle**

[scalar] angle of rotation, in radians.

**Returns****A**

[array shape (4, 4)] Affine array to be multiplied on left of coordinate column vector to apply given rotation.

**Notes**

Applying a rotation around a point is the same as applying a translation of `-point` to move `point` to the origin, rotating, then applying a translation of `point`. If `R` is the rotation matrix, then the affine for the rotation about point `P` is:

```
[R00, R01, R02, P0 - P0*R00 - P1*R01 - P2*R02]
[R10, R11, R12, P1 - P0*R10 - P1*R11 - P2*R12]
[R20, R21, R22, P2 - P0*R20 - P1*R21 - P2*R22]
[ 0, 0, 0, 1]
```

(see derivations)

**Examples**

```
>>> angle = (np.random.random() - 0.5) * (2*math.pi)
>>> direc = np.random.random(3) - 0.5
>>> point = np.random.random(3) - 0.5
>>> R0 = axangle2aff(direc, angle, point)
>>> R1 = axangle2aff(direc, angle-2*math.pi, point)
>>> np.allclose(R0, R1)
True
>>> R0 = axangle2aff(direc, angle, point)
>>> R1 = axangle2aff(-direc, -angle, point)
>>> np.allclose(R0, R1)
True
>>> I = np.identity(4, np.float64)
>>> np.allclose(I, axangle2aff(direc, math.pi*2))
True
>>> np.allclose(2., np.trace(axangle2aff(direc,
...                                     math.pi/2,
...                                     point)))
True
```

### 4.5.3 axangle2mat

transforms3d.axes.**axangle2mat**(*axis*, *angle*, *is\_normalized=False*)Rotation matrix for rotation angle *angle* around *axis***Parameters****axis**

[3 element sequence] vector specifying axis for rotation.

**angle**

[scalar] angle of rotation in radians.

**is\_normalized**[bool, optional] True if *axis* is already normalized (has norm of 1). Default False.**Returns****mat**

[array shape (3,3)] rotation matrix for specified rotation

**Notes**From: [http://en.wikipedia.org/wiki/Rotation\\_matrix#Axis\\_and\\_angle](http://en.wikipedia.org/wiki/Rotation_matrix#Axis_and_angle)

## 4.5.4 mat2axangle

transforms3d.axangles.**mat2axangle**(*mat*, *unit\_thresh=1e-05*)Return axis, angle and point from (3, 3) matrix *mat***Parameters****mat**

[array-like shape (3, 3)] Rotation matrix

**unit\_thresh**[float, optional] Tolerable difference from 1 when testing for unit eigenvalues to confirm *mat* is a rotation matrix.**Returns****axis**

[array shape (3,)] vector giving axis of rotation

**angle**

[scalar] angle of rotation in radians.

**Notes**[http://en.wikipedia.org/wiki/Rotation\\_matrix#Axis\\_of\\_a\\_rotation](http://en.wikipedia.org/wiki/Rotation_matrix#Axis_of_a_rotation)**Examples**

```

>>> direc = np.random.random(3) - 0.5
>>> angle = (np.random.random() - 0.5) * (2*math.pi)
>>> R0 = axangle2mat(direc, angle)
>>> direc, angle = mat2axangle(R0)
>>> R1 = axangle2mat(direc, angle)
>>> np.allclose(R0, R1)
True

```

## 4.6 derivations

=

### 4.6.1 Module: derivations.angle\_axes

Derivations for rotations of angle around axis

<code>angle_axis2mat(theta, vector)</code>	Rotation matrix of angle <i>theta</i> around <i>vector</i>
<code>angle_axis2quat(theta, vector)</code>	Quaternion for rotation of angle <i>theta</i> around <i>vector</i> Notes ----- Formula from <a href="http://mathworld.wolfram.com/EulerParameters.html">http://mathworld.wolfram.com/EulerParameters.html</a>
<code>orig_aa2mat(angle, direction)</code>	
<code>quat2angle_axis(quat)</code>	Convert quaternion to rotation of angle around axis

## 4.6.2 Module: `derivations.decompositions`

Derivations for extracting rotations, zooms, shears

==

## 4.6.3 Module: `derivations.eulerangles`

These give the derivations for Euler angles to rotation matrix and Euler angles to quaternion. We use the rotation matrix derivation only in the tests. The quaternion derivation is in the tests, and, in more compact form, in the `euler2quat` code.

The rotation matrices operate on column vectors, thus, if *R* is the 3x3 rotation matrix, *v* is the 3 x *N* set of *N* vectors to be rotated, and *vdash* is the matrix of rotated vectors:

```
vdash = np.dot(R, v)
```

<code>x_rotation(theta)</code>	Rotation angle <i>theta</i> around x-axis <a href="http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three">http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three</a>
<code>y_rotation(theta)</code>	Rotation angle <i>theta</i> around y-axis <a href="http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three">http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three</a>
<code>z_rotation(theta)</code>	Rotation angle <i>theta</i> around z-axis <a href="http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three">http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three</a>

## 4.6.4 Module: `derivations.quaternions`

Symbolic formulae for quaternions

<code>qmult(q1, q2)</code>	Multiply two quaternions
<code>quat2mat(quat)</code>	Symbolic conversion from quaternion to rotation matrix
<code>quat_around_axis(theta, axis)</code>	Quaternion for rotation of angle <i>theta</i> around axis <i>axis</i>

## 4.6.5 Module: `derivations.utils`

Utilities for derivations

```
make_matrix(name_prefix, N, M)

matrices_equal(M1, M2)
```

continues on next page



Table 11 – continued from previous page

`matrix_simplify(M)`**angle\_axis2mat**`transforms3d.derivations.angle_axes.angle_axis2mat(theta, vector)`Rotation matrix of angle *theta* around *vector***Parameters****theta**

[scalar] angle of rotation

**vector**

[3 element sequence] vector specifying axis for rotation.

**is\_normalized**

[bool, optional] True if vector is already normalized (has norm of 1). Default False

**Returns****mat**

[array shape (3,3)] rotation matrix specified rotation

**Notes**From: [http://en.wikipedia.org/wiki/Rotation\\_matrix#Axis\\_and\\_angle](http://en.wikipedia.org/wiki/Rotation_matrix#Axis_and_angle)**angle\_axis2quat**`transforms3d.derivations.angle_axes.angle_axis2quat(theta, vector)`Quaternion for rotation of angle *theta* around *vector* Notes — Formula from <http://mathworld.wolfram.com/EulerParameters.html>**orig\_aa2mat**`transforms3d.derivations.angle_axes.orig_aa2mat(angle, direction)`**quat2angle\_axis**`transforms3d.derivations.angle_axes.quat2angle_axis(quat)`

Convert quaternion to rotation of angle around axis

**x\_rotation**`transforms3d.derivations.eulerangles.x_rotation(theta)`Rotation angle *theta* around x-axis [http://en.wikipedia.org/wiki/Rotation\\_matrix#Dimension\\_three](http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three)**y\_rotation**`transforms3d.derivations.eulerangles.y_rotation(theta)`Rotation angle *theta* around y-axis [http://en.wikipedia.org/wiki/Rotation\\_matrix#Dimension\\_three](http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three)

### z\_rotation

`transforms3d.derivations.eulerangles.z_rotation(theta)`

Rotation angle *theta* around z-axis [http://en.wikipedia.org/wiki/Rotation\\_matrix#Dimension\\_three](http://en.wikipedia.org/wiki/Rotation_matrix#Dimension_three)

### qmult

`transforms3d.derivations.quaternions.qmult(q1, q2)`

Multiply two quaternions

#### Parameters

**q1**  
[4 element sequence]

**q2**  
[4 element sequence]

#### Returns

**q12**  
[shape (4,) array]

#### Notes

See : [http://en.wikipedia.org/wiki/Quaternions#Hamilton\\_product](http://en.wikipedia.org/wiki/Quaternions#Hamilton_product)

### quat2mat

`transforms3d.derivations.quaternions.quat2mat(quat)`

Symbolic conversion from quaternion to rotation matrix

For a unit quaternion

From: [http://en.wikipedia.org/wiki/Rotation\\_matrix#Quaternion](http://en.wikipedia.org/wiki/Rotation_matrix#Quaternion)

### quat\_around\_axis

`transforms3d.derivations.quaternions.quat_around_axis(theta, axis)`

Quaternion for rotation of angle *theta* around axis *axis*

#### Parameters

**theta**  
[symbol] angle of rotation

**axis**  
[3 element sequence] vector (assumed normalized) specifying axis for rotation

#### Returns

**quat**  
[4 element sequence of symbols] quaternion giving specified rotation

#### Notes

Formula from <http://mathworld.wolfram.com/EulerParameters.html>

**make\_matrix**

`transforms3d.derivations.utils.make_matrix(name_prefix, N, M)`

**matrices\_equal**

`transforms3d.derivations.utils.matrices_equal(M1, M2)`

**matrix\_simplify**

`transforms3d.derivations.utils.matrix_simplify(M)`

## 4.7 euler

Generic Euler rotations

See:

- [http://en.wikipedia.org/wiki/Rotation\\_matrix](http://en.wikipedia.org/wiki/Rotation_matrix)
- [http://en.wikipedia.org/wiki/Euler\\_angles](http://en.wikipedia.org/wiki/Euler_angles)
- <http://mathworld.wolfram.com/EulerAngles.html>

See also: *Representing Attitude with Euler Angles and Quaternions: A Reference* (2006) by James Diebel. A cached PDF link last found here:

<http://citeseerx.ist.psu.edu/viewdoc/summary?doi=10.1.1.110.5134>

### 4.7.1 Defining rotations

Euler's rotation theorem tells us that any rotation in 3D can be described by 3 angles. Let's call the 3 angles the *Euler angle vector* and call the angles in the vector *alpha*, *beta* and *gamma*. The vector is [ *alpha*, *beta*, *gamma* ] and, in this description, the order of the parameters specifies the order in which the rotations occur (so the rotation corresponding to *alpha* is applied first).

In order to specify the meaning of an *Euler angle vector* we need to specify the axes around which each of the rotations corresponding to *alpha*, *beta* and *gamma* will occur.

There are therefore three axes for the rotations *alpha*, *beta* and *gamma*; let's call them *i*, *j*, *k*.

Let us express the rotation *alpha* around axis *i* as a 3 by 3 rotation matrix *A*. Similarly *beta* around *j* becomes 3 x 3 matrix *B* and *gamma* around *k* becomes matrix *G*. Then the whole rotation expressed by the Euler angle vector [ *alpha*, *beta*, *gamma* ], *R* is given by:

```
R = np.dot(G, np.dot(B, A))
```

See <http://mathworld.wolfram.com/EulerAngles.html>

The order *GBA* expresses the fact that the rotations are performed in the order of the vector (*alpha* around axis *i* = *A* first).

To convert a given Euler angle vector to a meaningful rotation, and a rotation matrix, we need to define:

- the axes *i*, *j*, *k*;
- whether the rotations move the axes as they are applied (intrinsic rotations) - compared the situation where the axes stay fixed and the vectors move within the axis frame (extrinsic);
- whether a rotation matrix should be applied on the left of a vector to be transformed (vectors are column vectors) or on the right (vectors are row vectors);

- the handedness of the coordinate system.

See: [http://en.wikipedia.org/wiki/Rotation\\_matrix#Ambiguities](http://en.wikipedia.org/wiki/Rotation_matrix#Ambiguities)

This module implements intrinsic and extrinsic axes, with standard conventions for axes  $i, j, k$ . We assume that the matrix should be applied on the left of the vector, and right-handed coordinate systems. To get the matrix to apply on the right of the vector, you need the transpose of the matrix we supply here, by the matrix transpose rule:  $(M.V)^T = V^T M^T$ .

## 4.7.2 Rotation axes

Rotations given as a set of three angles can refer to any of 24 different ways of applying these rotations, or equivalently, 24 conventions for rotation angles. See [http://en.wikipedia.org/wiki/Euler\\_angles](http://en.wikipedia.org/wiki/Euler_angles).

The different conventions break down into two groups of 12. In the first group, the rotation axes are fixed (also, global, static), and do not move with rotations. These are called *extrinsic* axes. The axes can also move with the rotations. These are called *intrinsic*, local or rotating axes.

Each of the two groups (*intrinsic* and *extrinsic*) can further be divided into so-called Euler rotations (rotation about one axis, then a second and then the first again), and Tait-Bryan angles (rotations about all three axes). The two groups (Euler rotations and Tait-Bryan rotations) each have 6 possible choices. There are therefore  $2 * 2 * 6 = 24$  possible conventions that could apply to rotations about a sequence of three given angles.

This module gives an implementation of conversion between angles and rotation matrices for which you can specify any of the 24 different conventions.

## 4.7.3 Specifying angle conventions

You specify conventions for interpreting the sequence of angles with a four character string.

The first character is 'r' (rotating == intrinsic), or 's' (static == extrinsic).

The next three characters give the axis ('x', 'y' or 'z') about which to perform the rotation, in the order in which the rotations will be performed.

For example the string 'szyx' specifies that the angles should be interpreted relative to extrinsic (static) coordinate axes, and be performed in the order: rotation about z axis; rotation about y axis; rotation about x axis. This is a relatively common convention, with customized implementations in `taitbryan` in this package.

The string 'rxzx' specifies that the angles should be interpreted relative to intrinsic (rotating) coordinate axes, and be performed in the order: rotation about z axis; rotation about the rotated x axis; rotation about the rotated z axis. Wolfram Mathworld claim this is the most common convention : <http://mathworld.wolfram.com/EulerAngles.html>.

## 4.7.4 Direction of rotation

The direction of rotation is given by the right-hand rule (orient the thumb of the right hand along the axis around which the rotation occurs, with the end of the thumb at the positive end of the axis; curl your fingers; the direction your fingers curl is the direction of rotation). Therefore, the rotations are counterclockwise if looking along the axis of rotation from positive to negative.

## 4.7.5 Terms used in function names

- *mat* : array shape (3, 3) (3D non-homogenous coordinates)
- *euler* : (sequence of) rotation angles about the z, y, x axes (in that order)
- *axangle* : rotations encoded by axis vector and angle scalar
- *quat* : quaternion shape (4,)

<code>EulerFuncs</code> (axes)	Namespace for Euler angles functions with given axes specification
<code>TBZYX</code> ()	Namespace for Tait-Bryan ZYX Euler angle convention functions
<code>axangle2euler</code> (vector, theta[, axes])	Convert axis, angle pair to Euler angles
<code>euler2axangle</code> (ai, aj, ak[, axes])	Return angle, axis corresponding to Euler angles, axis specification
<code>euler2mat</code> (ai, aj, ak[, axes])	Return rotation matrix from Euler angles and axis sequence.
<code>euler2quat</code> (ai, aj, ak[, axes])	Return <i>quaternion</i> from Euler angles and axis sequence <i>axes</i>
<code>mat2euler</code> (mat[, axes])	Return Euler angles from rotation matrix for specified axis sequence.
<code>quat2euler</code> (quaternion[, axes])	Euler angles from <i>quaternion</i> for specified axis sequence <i>axes</i>

### 4.7.6 EulerFuncs

**class** transforms3d.euler.**EulerFuncs**(*axes*)

Bases: object

Namespace for Euler angles functions with given axes specification

**\_\_init\_\_**(*axes*)

Initialize namespace for Euler angles functions

#### Parameters

**axes**

[str] Axis specification; one of 24 axis sequences as string or encoded tuple - e.g. `sxyz` (the default).

**axangle2euler**(*vector*, *theta*)

Convert axis, angle pair to Euler angles

See [axangle2euler\(\)](#) for details.

**euler2axangle**(*ai*, *aj*, *ak*)

Angle, axis corresponding to Euler angles

See [euler2axangle\(\)](#) for details.

**euler2mat**(*ai*, *aj*, *ak*)

Return rotation matrix from Euler angles

See [euler2mat\(\)](#) for details.

**euler2quat**(*ai*, *aj*, *ak*)

Return *quaternion* from Euler angles

See [euler2quat\(\)](#) for details.

**mat2euler**(*mat*)

Return Euler angles from rotation matrix *mat*

See [mat2euler\(\)](#) for details.

**quat2euler**(*quat*)

Euler angles from *quaternion*

See [quat2euler\(\)](#) for details.

#### 4.7.7 TBZYX

**class** transforms3d.euler.TBZYX

Bases: [EulerFuncs](#)

Namespace for Tait-Bryan ZYX Euler angle convention functions

**\_\_init\_\_**()

Initialize Tait-Bryan ZYX namespace

**euler2mat**(*ai, aj, ak*)

Return rotation matrix from Euler angles

See [transforms3d.taitbryan.euler2mat\(\)](#) for details.

**euler2quat**(*ai, aj, ak*)

Return *quaternion* from Euler angles

See [transforms3d.taitbryan.euler2quat\(\)](#) for details.

**mat2euler**(*mat*)

Return Euler angles from rotation matrix *mat*

See [transforms3d.taitbryan.mat2euler\(\)](#) for details.

#### 4.7.8 axangle2euler

transforms3d.euler.**axangle2euler**(*vector, theta, axes='sxyz'*)

Convert axis, angle pair to Euler angles

##### Parameters

**vector**

[3 element sequence] vector specifying axis for rotation.

**theta**

[scalar] angle of rotation

**axes**

[str, optional] Axis specification; one of 24 axis sequences as string or encoded tuple - e.g. sxyz (the default).

##### Returns

**ai**

[float] First rotation angle (according to *axes*).

**aj**

[float] Second rotation angle (according to *axes*).

**ak**

[float] Third rotation angle (according to *axes*).

### Examples

```
>>> ai, aj, ak = axangle2euler([1, 0, 0], 0)
>>> np.allclose((ai, aj, ak), 0)
True
```

## 4.7.9 euler2axangle

transforms3d.euler.**euler2axangle**(*ai, aj, ak, axes='sxyz'*)

Return angle, axis corresponding to Euler angles, axis specification

### Parameters

- ai**  
[float] First rotation angle (according to *axes*).
- aj**  
[float] Second rotation angle (according to *axes*).
- ak**  
[float] Third rotation angle (according to *axes*).
- axes**  
[str, optional] Axis specification; one of 24 axis sequences as string or encoded tuple - e.g. *sxyz* (the default).

### Returns

- vector**  
[array shape (3,)] axis around which rotation occurs
- theta**  
[scalar] angle of rotation

### Examples

```
>>> vec, theta = euler2axangle(0, 1.5, 0, 'szyx')
>>> np.allclose(vec, [0, 1, 0])
True
>>> theta
1.5
```

## 4.7.10 euler2mat

transforms3d.euler.**euler2mat**(*ai, aj, ak, axes='sxyz'*)

Return rotation matrix from Euler angles and axis sequence.

### Parameters

- ai**  
[float] First rotation angle (according to *axes*).
- aj**  
[float] Second rotation angle (according to *axes*).
- ak**  
[float] Third rotation angle (according to *axes*).

**axes**

[str, optional] Axis specification; one of 24 axis sequences as string or encoded tuple - e.g. `sxyz` (the default).

**Returns**

**mat**

[array (3, 3)] Rotation matrix or affine.

### Examples

```
>>> R = euler2mat(1, 2, 3, 'sxyz')
>>> np.allclose(np.sum(R[0]), -1.34786452)
True
>>> R = euler2mat(1, 2, 3, (0, 1, 0, 1))
>>> np.allclose(np.sum(R[0]), -0.383436184)
True
```

## 4.7.11 euler2quat

`transforms3d.euler.euler2quat(ai, aj, ak, axes='sxyz')`

Return *quaternion* from Euler angles and axis sequence *axes*

**Parameters**

**ai**

[float] First rotation angle (according to *axes*).

**aj**

[float] Second rotation angle (according to *axes*).

**ak**

[float] Third rotation angle (according to *axes*).

**axes**

[str, optional] Axis specification; one of 24 axis sequences as string or encoded tuple - e.g. `sxyz` (the default).

**Returns**

**quat**

[array shape (4,)] Quaternion in w, x, y, z (real, then vector) format

### Examples

```
>>> q = euler2quat(1, 2, 3, 'ryxz')
>>> np.allclose(q, [0.435953, 0.310622, -0.718287, 0.444435])
True
```

## 4.7.12 mat2euler

`transforms3d.euler.mat2euler(mat, axes='sxyz')`

Return Euler angles from rotation matrix for specified axis sequence.

Note that many Euler angle triplets can describe one matrix.

**Parameters**



**mat**

[array-like shape (3, 3) or (4, 4)] Rotation matrix or affine.

**axes**[str, optional] Axis specification; one of 24 axis sequences as string or encoded tuple - e.g. `sxyz` (the default).**Returns****ai**[float] First rotation angle (according to *axes*).**aj**[float] Second rotation angle (according to *axes*).**ak**[float] Third rotation angle (according to *axes*).**Examples**

```
>>> R0 = euler2mat(1, 2, 3, 'syxz')
>>> al, be, ga = mat2euler(R0, 'syxz')
>>> R1 = euler2mat(al, be, ga, 'syxz')
>>> np.allclose(R0, R1)
True
```

### 4.7.13 quat2euler

`transforms3d.euler.quat2euler(quaternion, axes='sxyz')`Euler angles from *quaternion* for specified axis sequence *axes***Parameters****q**

[4 element sequence] w, x, y, z of quaternion

**axes**[str, optional] Axis specification; one of 24 axis sequences as string or encoded tuple - e.g. `sxyz` (the default).**Returns****ai**[float] First rotation angle (according to *axes*).**aj**[float] Second rotation angle (according to *axes*).**ak**[float] Third rotation angle (according to *axes*).**Examples**

```
>>> angles = quat2euler([0.99810947, 0.06146124, 0, 0])
>>> np.allclose(angles, [0.123, 0, 0])
True
```

## 4.8 quaternions

Functions to operate on, or return, quaternions.

Quaternions here consist of 4 values  $w$ ,  $x$ ,  $y$ ,  $z$ , where  $w$  is the real (scalar) part, and  $x$ ,  $y$ ,  $z$  are the complex (vector) part.

Note - rotation matrices here apply to column vectors, that is, they are applied on the left of the vector. For example:

```
>>> import numpy as np
>>> q = [0, 1, 0, 0] # 180 degree rotation around axis 0
>>> M = quat2mat(q) # from this module
>>> vec = np.array([1, 2, 3]).reshape((3,1)) # column vector
>>> tvec = np.dot(M, vec)
```

Terms used in function names:

- *mat* : array shape (3, 3) (3D non-homogenous coordinates)
- *aff* : affine array shape (4, 4) (3D homogenous coordinates)
- *quat* : quaternion shape (4,)
- *axangle* : rotations encoded by axis vector and angle scalar

<i>axangle2quat</i> (vector, theta[, is_normalized])	Quaternion for rotation of angle <i>theta</i> around <i>vector</i>
<i>fillpositive</i> (xyz[, w2_thresh])	Compute unit quaternion from last 3 values
<i>mat2quat</i> (M)	Calculate quaternion corresponding to given rotation matrix
<i>nearly_equivalent</i> (q1, q2[, rtol, atol])	Returns True if <i>q1</i> and <i>q2</i> give near equivalent transforms
<i>qconjugate</i> (q)	Conjugate of quaternion
<i>qexp</i> (q)	Return exponential of quaternion
<i>qeye</i> ([dtype])	Return identity quaternion
<i>qinverse</i> (q)	Return multiplicative inverse of quaternion <i>q</i>
<i>qisunit</i> (q)	Return True if this is very nearly a unit quaternion
<i>qlog</i> (q)	Return natural logarithm of quaternion
<i>qmult</i> (q1, q2)	Multiply two quaternions
<i>qnorm</i> (q)	Return norm of quaternion
<i>qpow</i> (q, n)	Return the <i>n</i> th power of quaternion <i>q</i>
<i>quat2axangle</i> (quat[, identity_thresh])	Convert quaternion to rotation of angle around axis
<i>quat2mat</i> (q)	Calculate rotation matrix corresponding to quaternion
<i>rotate_vector</i> (v, q[, is_normalized])	Apply transformation in quaternion <i>q</i> to vector <i>v</i>

### 4.8.1 axangle2quat

transforms3d.quaternions.**axangle2quat**(vector, theta, is\_normalized=False)

Quaternion for rotation of angle *theta* around *vector*

#### Parameters

##### vector

[3 element sequence] vector specifying axis for rotation.

##### theta

[scalar] angle of rotation in radians.

**is\_normalized**

[bool, optional] True if vector is already normalized (has norm of 1). Default False.

**Returns****quat**

[4 element sequence of symbols] quaternion giving specified rotation

**Notes**

Formula from <http://mathworld.wolfram.com/EulerParameters.html>

**Examples**

```
>>> q = axangle2quat([1, 0, 0], np.pi)
>>> np.allclose(q, [0, 1, 0, 0])
True
```

## 4.8.2 fillpositive

`transforms3d.quaternions.fillpositive(xyz, w2_thresh=None)`

Compute unit quaternion from last 3 values

**Parameters****xyz**

[iterable] iterable containing 3 values, corresponding to quaternion x, y, z

**w2\_thresh**

[None or float, optional] threshold to determine if w squared is really negative. If None (default) then w2\_thresh set equal to `-np.finfo(xyz.dtype).eps`, if possible, otherwise `-np.finfo(np.float64).eps`

**Returns****wxyz**

[array shape (4,)] Full 4 values of quaternion

**Notes**

If w, x, y, z are the values in the full quaternion, assumes w is positive.

Gives error if  $w^2$  is estimated to be negative

$w = 0$  corresponds to a 180 degree rotation

The unit quaternion specifies that `np.dot(wxyz, wxyz) == 1`.

If w is positive (assumed here), w is given by:

$$w = \sqrt{1.0 - (x^2 + y^2 + z^2)}$$

$w^2 = 1.0 - (x^2 + y^2 + z^2)$  can be near zero, which will lead to numerical instability in sqrt. Here we use the system maximum float type to reduce numerical instability

**Examples**

```
>>> import numpy as np
>>> wxyz = fillpositive([0,0,0])
>>> assert np.all(wxyz == [1, 0, 0, 0])
>>> wxyz = fillpositive([1,0,0]) # Corner case; w is 0
>>> assert np.all(wxyz == [0, 1, 0, 0])
>>> assert np.dot(wxyz, wxyz) == 1
```

### 4.8.3 mat2quat

transforms3d.quaternions.**mat2quat**(*M*)

Calculate quaternion corresponding to given rotation matrix

Method claimed to be robust to numerical errors in *M*.

Constructs quaternion by calculating maximum eigenvector for matrix *K* (constructed from input *M*). Although this is not tested, a maximum eigenvalue of 1 corresponds to a valid rotation.

A quaternion  $q^* - 1$  corresponds to the same rotation as  $q$ ; thus the sign of the reconstructed quaternion is arbitrary, and we return quaternions with positive *w* ( $q[0]$ ).

See notes.

#### Parameters

*M*

[array-like] 3x3 rotation matrix

#### Returns

*q*

[(4,) array] closest quaternion to input matrix, having positive  $q[0]$

#### Notes

[http://en.wikipedia.org/wiki/Rotation\\_matrix#Quaternion](http://en.wikipedia.org/wiki/Rotation_matrix#Quaternion)

Bar-Itzhack, Itzhack Y. (2000), “New method for extracting the quaternion from a rotation matrix”, AIAA Journal of Guidance, Control and Dynamics 23(6):1085-1087 (Engineering Note), ISSN 0731-5090

#### References

- [http://en.wikipedia.org/wiki/Rotation\\_matrix#Quaternion](http://en.wikipedia.org/wiki/Rotation_matrix#Quaternion)
- Bar-Itzhack, Itzhack Y. (2000), “New method for extracting the quaternion from a rotation matrix”, AIAA Journal of Guidance, Control and Dynamics 23(6):1085-1087 (Engineering Note), ISSN 0731-5090

#### Examples

```
>>> import numpy as np
>>> q = mat2quat(np.eye(3)) # Identity rotation
>>> np.allclose(q, [1, 0, 0, 0])
True
>>> q = mat2quat(np.diag([1, -1, -1]))
>>> np.allclose(q, [0, 1, 0, 0]) # 180 degree rotn around axis 0
True
```

#### 4.8.4 nearly\_equivalent

`transforms3d.quaternions.nearly_equivalent(q1, q2, rtol=1e-05, atol=1e-08)`

Returns True if  $q1$  and  $q2$  give near equivalent transforms

$q1$  may be nearly numerically equal to  $q2$ , or nearly equal to  $q2 * -1$  (because a quaternion multiplied by -1 gives the same transform).

##### Parameters

**q1**

[4 element sequence] w, x, y, z of first quaternion

**q2**

[4 element sequence] w, x, y, z of second quaternion

##### Returns

**equiv**

[bool] True if  $q1$  and  $q2$  are nearly equivalent, False otherwise

##### Examples

```
>>> q1 = [1, 0, 0, 0]
>>> nearly_equivalent(q1, [0, 1, 0, 0])
False
>>> nearly_equivalent(q1, [1, 0, 0, 0])
True
>>> nearly_equivalent(q1, [-1, 0, 0, 0])
True
```

#### 4.8.5 qconjugate

`transforms3d.quaternions.qconjugate(q)`

Conjugate of quaternion

##### Parameters

**q**

[4 element sequence] w, i, j, k of quaternion

##### Returns

**conjq**

[array shape (4,)] w, i, j, k of conjugate of  $q$

#### 4.8.6 qexp

`transforms3d.quaternions.qexp(q)`

Return exponential of quaternion

##### Parameters

**q**

[4 element sequence] w, i, j, k of quaternion

##### Returns

**q\_exp**

[array shape (4,)] The quaternion exponential

## Notes

See:

- [https://en.wikipedia.org/wiki/Quaternion#Exponential,\\_logarithm,\\_and\\_power](https://en.wikipedia.org/wiki/Quaternion#Exponential,_logarithm,_and_power)
- <https://math.stackexchange.com/questions/1030737/exponential-function-of-quaternion-derivation>

### 4.8.7 qeye

`transforms3d.quaternions.qeye(dtype=<class 'numpy.float64'>)`

Return identity quaternion

### 4.8.8 qinverse

`transforms3d.quaternions.qinverse(q)`

Return multiplicative inverse of quaternion  $q$

#### Parameters

**q**  
[4 element sequence] w, i, j, k of quaternion

#### Returns

**invq**  
[array shape (4,)] w, i, j, k of quaternion inverse

### 4.8.9 qisunit

`transforms3d.quaternions.qisunit(q)`

Return True if this is very nearly a unit quaternion

### 4.8.10 qlog

`transforms3d.quaternions.qlog(q)`

Return natural logarithm of quaternion

#### Parameters

**q**  
[4 element sequence] w, i, j, k of quaternion

#### Returns

**q\_log**  
[array shape (4,)] Natural logarithm of quaternion

## Notes

See: [https://en.wikipedia.org/wiki/Quaternion#Exponential,\\_logarithm,\\_and\\_power](https://en.wikipedia.org/wiki/Quaternion#Exponential,_logarithm,_and_power)

### 4.8.11 qmult

`transforms3d.quaternions.qmult(q1, q2)`

Multiply two quaternions

#### Parameters

**q1**  
[4 element sequence]

**q2**  
[4 element sequence]

**Returns**

**q12**  
[shape (4,) array]

**Notes**

See : [http://en.wikipedia.org/wiki/Quaternions#Hamilton\\_product](http://en.wikipedia.org/wiki/Quaternions#Hamilton_product)

### 4.8.12 qnorm

transforms3d.quaternions.**qnorm**(*q*)

Return norm of quaternion

**Parameters**

**q**  
[4 element sequence] w, i, j, k of quaternion

**Returns**

**n**  
[scalar] quaternion norm

**Notes**

<http://mathworld.wolfram.com/QuaternionNorm.html>

### 4.8.13 qpow

transforms3d.quaternions.**qpow**(*q*, *n*)

Return the *n* th power of quaternion *q*

**Parameters**

**q**  
[4 element sequence] w, i, j, k of quaternion

**n**  
[int or float] A real number

**Returns**

**q\_pow**  
[array shape (4,)] The quaternion *q* to *n* th power.

**Notes**

See: [https://en.wikipedia.org/wiki/Quaternion#Exponential,\\_logarithm,\\_and\\_power](https://en.wikipedia.org/wiki/Quaternion#Exponential,_logarithm,_and_power)

### 4.8.14 quat2axangle

transforms3d.quaternions.**quat2axangle**(quat, identity\_thresh=None)

Convert quaternion to rotation of angle around axis

#### Parameters

##### quat

[4 element sequence] w, x, y, z forming quaternion.

##### identity\_thresh

[None or scalar, optional] Threshold below which the norm of the vector part of the quaternion (x, y, z) is deemed to be 0, leading to the identity rotation. None (the default) leads to a threshold estimated based on the precision of the input.

#### Returns

##### theta

[scalar] angle of rotation.

##### vector

[array shape (3,)] axis around which rotation occurs.

#### Notes

A quaternion for which x, y, z are all equal to 0, is an identity rotation. In this case we return a 0 angle and an arbitrary vector, here [1, 0, 0].

The algorithm allows for quaternions that have not been normalized.

#### Examples

```
>>> vec, theta = quat2axangle([0, 1, 0, 0])
>>> vec
array([1., 0., 0.])
>>> np.allclose(theta, np.pi)
True
```

If this is an identity rotation, we return a zero angle and an arbitrary vector:

```
>>> quat2axangle([1, 0, 0, 0])
(array([1., 0., 0.]), 0.0)
```

If any of the quaternion values are not finite, we return a NaN in the angle, and an arbitrary vector:

```
>>> quat2axangle([1, np.inf, 0, 0])
(array([1., 0., 0.]), nan)
```

### 4.8.15 quat2mat

transforms3d.quaternions.**quat2mat**(q)

Calculate rotation matrix corresponding to quaternion

#### Parameters

##### q

[4 element array-like]

#### Returns



**M**

[(3,3) array] Rotation matrix corresponding to input quaternion  $q$

**Notes**

Rotation matrix applies to column vectors, and is applied to the left of coordinate vectors. The algorithm here allows quaternions that have not been normalized.

**References**

Algorithm from [http://en.wikipedia.org/wiki/Rotation\\_matrix#Quaternion](http://en.wikipedia.org/wiki/Rotation_matrix#Quaternion)

**Examples**

```
>>> import numpy as np
>>> M = quat2mat([1, 0, 0, 0]) # Identity quaternion
>>> np.allclose(M, np.eye(3))
True
>>> M = quat2mat([0, 1, 0, 0]) # 180 degree rotn around axis 0
>>> np.allclose(M, np.diag([1, -1, -1]))
True
```

**4.8.16 rotate\_vector**

`transforms3d.quaternions.rotate_vector(v, q, is_normalized=True)`

Apply transformation in quaternion  $q$  to vector  $v$

**Parameters**

**v**

[3 element sequence] 3 dimensional vector

**q**

[4 element sequence] w, i, j, k of quaternion

**is\_normalized**

[{True, False}, optional] If True, assume  $q$  is normalized. If False, normalize  $q$  before applying.

**Returns**

**vdash**

[array shape (3,)]  $v$  rotated by quaternion  $q$

**Notes**

See: [http://en.wikipedia.org/wiki/Quaternions\\_and\\_spatial\\_rotation#Describing\\_rotations\\_with\\_quaternions](http://en.wikipedia.org/wiki/Quaternions_and_spatial_rotation#Describing_rotations_with_quaternions)

**4.9 reflections**

Functions to work with reflections

Terms used in function names:

- *mat* : array shape (3, 3) (3D non-homogenous coordinates)
- *aff* : affine array shape (4, 4) (3D homogenous coordinates)
- *rfnorm* : reflection in plane defined by normal vector and optional point.

<code>aff2rfnorm(aff)</code>	Mirror plane normal vector and point from affine <i>aff</i>
<code>mat2rfnorm(mat)</code>	Mirror plane normal vector from <i>mat</i> matrix.
<code>rfnorm2aff(normal[, point])</code>	Affine to mirror at plane defined by point and normal vector.
<code>rfnorm2mat(normal)</code>	Matrix to reflect in plane through origin, orthogonal to <i>normal</i>

---

### 4.9.1 aff2rfnorm

`transforms3d.reflections.aff2rfnorm(aff)`

Mirror plane normal vector and point from affine *aff*

#### Parameters

**aff**

[array-like, shape (4,4)]

#### Returns

**normal**

[array shape (3,)] vector normal to point (and therefore mirror plane).

**point**

[array shape (3,)] x, y, x coordinates of point that, together with normal, define the reflection plane.

#### Raises

**ValueError**

If there is no eigenvector for `aff[:3, :3]` with eigenvalue -1

**ValueError**

If determinant of `aff[:3, :3]` is not close to -1

**ValueError**

If there is no eigenvector for *aff* with eigenvalue 1.

#### Examples

```
>>> v0 = np.random.random(3) - 0.5
>>> v1 = np.random.random(3) - 0.5
>>> M0 = rfnorm2aff(v0, v1)
>>> normal, point = aff2rfnorm(M0)
>>> M1 = rfnorm2aff(normal, point)
>>> np.allclose(M0, M1)
True
```

### 4.9.2 mat2rfnorm

`transforms3d.reflections.mat2rfnorm(mat)`

Mirror plane normal vector from *mat* matrix.

#### Parameters

**mat**

[array-like, shape (3,3)]

**Returns****normal**

[array shape (3,)] vector normal to point (and therefore mirror plane)

**Raises****ValueError**

If there is no eigenvector with eigenvalue -1

**ValueError**

If determinant of *mat* is not close to -1

**Examples**

```
>>> normal = np.random.random(3) - 0.5
>>> M0 = rfnorm2mat(normal)
>>> normal = mat2rfnorm(M0)
>>> M1 = rfnorm2mat(normal)
>>> np.allclose(M0, M1)
True
```

**4.9.3 rfnorm2aff**

`transforms3d.reflections.rfnorm2aff(normal, point=None)`

Affine to mirror at plane defined by point and normal vector.

**Parameters****normal**

[3 element sequence] vector normal to point (and therefore mirror plane)

**point**

[3 element sequence] x, y, x coordinates of point

**Returns****aff**

[array shape (4,4)]

**Notes**

See [`rfnorm2mat\(\)`](#)

**Examples**

```
>>> normal = np.random.random(3) - 0.5
>>> point = np.random.random(3) - 0.5
>>> R = rfnorm2aff(normal, point)
>>> np.allclose(2., np.trace(R))
True
>>> np.allclose(point, np.dot(R[:3,:3], point) + R[:3,3])
True
```

## 4.9.4 rfnorm2mat

`transforms3d.reflections.rfnorm2mat(normal)`

Matrix to reflect in plane through origin, orthogonal to *normal*

### Parameters

#### **normal**

[array-like, shape (3,)] vector normal to plane of reflection

### Returns

#### **mat**

[array shape (3,3)]

### Notes

[http://en.wikipedia.org/wiki/Reflection\\_\(mathematics\)](http://en.wikipedia.org/wiki/Reflection_(mathematics))

The reflection of a vector  $v$  in a plane normal to vector  $a$  is:

$$\text{Ref}_a(v) = v - 2 \frac{v \cdot a}{a \cdot a} a$$

The entries of the corresponding orthogonal transformation matrix  $R$  are given by:

$$R_{ij} = I_{ij} - 2 \frac{a_i a_j}{\|a\|^2}$$

where  $I$  is the identity matrix.

## 4.10 shears

Functions for working with shears

Terms used in function names:

- *mat* : array shape (3, 3) (3D non-homogenous coordinates)
- *aff* : affine array shape (4, 4) (3D homogenous coordinates)
- *striu* : shears encoded by vector giving triangular portion above diagonal of NxN array (for ND transformation)
- *sadn* : shears encoded by angle scalar, direction vector, normal vector (with optional point vector)

<code>aff2sadn(aff)</code>	Return shear angle, direction and plane normal from shear matrix.
<code>inverse_outer(mat)</code>	Return scalar $t$ , unit vectors $a, b$ so $mat = t * np.outer(a, b)$
<code>mat2sadn(mat)</code>	Return shear angle, direction and plane normal from shear matrix.
<code>sadn2aff(angle, direction, normal[, point])</code>	Affine for shear by <i>angle</i> along vector <i>direction</i> on shear plane.
<code>sadn2mat(angle, direction, normal)</code>	Matrix for shear by <i>angle</i> along <i>direction</i> vector on shear plane.
<code>striu2mat(striu)</code>	Construct shear matrix from upper triangular vector

### 4.10.1 aff2sadr

`transforms3d.shears.aff2sadr(aff)`

Return shear angle, direction and plane normal from shear matrix.

#### Parameters

##### **mat**

[array-like, shape (3,3)] shear matrix.

#### Returns

##### **angle**

[scalar] angle to shear, in radians

##### **direction**

[array, shape (3,)] direction along which to shear

##### **normal**

[array, shape (3,)] vector normal to shear plane

##### **point**

[array, shape (3,)] point that, with *normal*, defines shear plane.

#### Notes

The translation part of the affine shear matrix is calculated using:

This holds for the  $i$ th coordinate:

Then:

This can be compared with the equation of the plane:

where  $d$  is the distance from the plane to the origin.

#### Examples

```
>>> A = sadn2aff(0.5, [1, 0, 0], [0, 1, 0])
>>> angle, direction, normal, point = aff2sadr(A)
>>> angle, direction, normal
(0.5, array([1., 0., 0.]), array([0., 1., 0.]))
>>> assert np.all(point == [0, 0, 0])
>>> A_again = sadn2aff(angle, direction, normal, point)
>>> np.allclose(A, A_again)
True
```

### 4.10.2 inverse\_outer

`transforms3d.shears.inverse_outer(mat)`

Return scalar  $t$ , unit vectors  $a, b$  so  $mat = t * np.outer(a, b)$

#### Parameters

##### **mat**

[array-like, shape (3,3)] shear matrix

#### Returns

##### **t**

[float] Scalar such that  $mat = t * np.outer(a, b)$

- a**  
[array, shape (3,)] Unit vector such that  $mat = t * np.outer(a, b)$
- b**  
[array, shape (3,)] Unit vector such that  $mat = t * np.outer(a, b)$

### 4.10.3 mat2sadb

transforms3d.shears.**mat2sadb**(*mat*)

Return shear angle, direction and plane normal from shear matrix.

#### Parameters

- mat**  
[array-like, shape (3,3)] shear matrix

#### Returns

- angle**  
[scalar] angle to shear, in radians
- direction**  
[array, shape (3,)] direction along which to shear
- normal**  
[array, shape (3,)] vector defining shear plane, where shear plane passes through origin

#### Notes

The shear matrix we are decomposing was calculated using:

So the idea is to use an “inverse outer product” to recover the shears. See [inverse\\_outer\(\)](#) for the implementation.

#### Examples

```
>>> M = sadn2mat(0.5, [1, 0, 0], [0, 1, 0])
>>> angle, direction, normal = mat2sadb(M)
>>> angle, direction, normal
(0.5, array([1., 0., 0.]), array([0., 1., 0.]))
>>> M_again = sadn2mat(angle, direction, normal)
>>> np.allclose(M, M_again)
True
```

### 4.10.4 sadn2aff

transforms3d.shears.**sadb2aff**(*angle, direction, normal, point=None*)

Affine for shear by *angle* along vector *direction* on shear plane.

The shear plane is defined by a point and normal vector. The direction vector must be orthogonal to the plane’s normal vector.

A point P is transformed by the shear matrix into P’ such that the vector P-P’ is parallel to the direction vector and its extent is given by the angle of P-P’-P’, where P’ is the orthogonal projection of P onto the shear plane.

#### Parameters

- angle**  
[scalar] angle to shear, in radians

**direction**

[array-like, shape (3,)] direction along which to shear

**normal**

[array-like, shape (3,)] vector normal to shear-plane

**point**

[None or array-like, shape (3,), optional] point, that, with *normal* defines shear plane. Defaults to None, equivalent to shear-plane through origin.

**Returns****aff**

[array shape (4,4)] affine shearing matrix

**Examples**

```
>>> angle = (np.random.random() - 0.5) * 4*math.pi
>>> direct = np.random.random(3) - 0.5
>>> normal = np.cross(direct, np.random.random(3))
>>> S = sadn2mat(angle, direct, normal)
>>> np.allclose(1.0, np.linalg.det(S))
True
```

### 4.10.5 sadn2mat

`transforms3d.shears.sadn2mat(angle, direction, normal)`

Matrix for shear by *angle* along *direction* vector on shear plane.

The shear plane is defined by normal vector *normal*, and passes through the origin. The direction vector must be orthogonal to the plane's normal vector.

A point P is transformed by the shear matrix into P'' such that the vector P-P'' is parallel to the direction vector and its extent is given by the angle of P-P'-P'', where P' is the orthogonal projection of P onto the shear plane.

**Parameters****angle**

[scalar] angle to shear, in radians

**direction**

[array-like, shape (3,)] direction along which to shear

**normal**

[array-like, shape (3,)] vector defining shear plane, where shear plane passes through origin

**Returns****mat**

[array shape (3,3)] shear matrix

**Examples**

```
>>> angle = (np.random.random() - 0.5) * 4*math.pi
>>> direct = np.random.random(3) - 0.5
>>> normal = np.cross(direct, np.random.random(3))
>>> S = sadn2aff(angle, direct, normal)
>>> np.allclose(1.0, np.linalg.det(S))
True
```

### 4.10.6 striu2mat

`transforms3d.shears.striu2mat(striu)`

Construct shear matrix from upper triangular vector

#### Parameters

##### **striu**

[array, shape (N,)] vector giving triangle above diagonal of shear matrix.

#### Returns

##### **SM**

[array, shape (N, N)] shear matrix

#### Notes

Shear lengths are triangular numbers.

See [http://en.wikipedia.org/wiki/Triangular\\_number](http://en.wikipedia.org/wiki/Triangular_number)

#### Examples

```
>>> S = [0.1, 0.2, 0.3]
>>> striu2mat(S)
array([[1. , 0.1, 0.2],
       [0. , 1. , 0.3],
       [0. , 0. , 1. ]])
>>> striu2mat([1])
array([[1., 1.],
       [0., 1.]])
>>> striu2mat([1, 2])
Traceback (most recent call last):
...
ValueError: 2 is a strange number of shear elements
```

## 4.11 taitbryan

Euler angle rotations and their conversions for Tait-Bryan zyx convention

See `euler` for general discussion of Euler angles and conventions.

This module has specialized implementations of the extrinsic Z axis, Y axis, X axis rotation convention.

The conventions in this module are therefore:

- axes  $i, j, k$  are the  $z, y, x$  axes respectively. Thus an Euler angle vector  $[\alpha, \beta, \gamma]$  in our convention implies a  $\alpha$  radian rotation around the  $z$  axis, followed by a  $\beta$  rotation around the  $y$  axis, followed by a  $\gamma$  rotation around the  $x$  axis.
- the rotation matrix applies on the left, to column vectors on the right, so if  $R$  is the rotation matrix, and  $v$  is a 3 x N matrix with N column vectors, the transformed vector set  $vdash$  is given by  $vdash = np.dot(R, v)$ .
- extrinsic rotations - the axes are fixed, and do not move with the rotations.
- a right-handed coordinate system

The convention of rotation around  $z$ , followed by rotation around  $y$ , followed by rotation around  $x$ , is known (confusingly) as “xyz”, pitch-roll-yaw, Cardan angles, or Tait-Bryan angles.



Terms used in function names:

- *mat* : array shape (3, 3) (3D non-homogenous coordinates)
- *euler* : (sequence of) rotation angles about the z, y, x axes (in that order)
- *axangle* : rotations encoded by axis vector and angle scalar
- *quat* : quaternion shape (4,)

<code>axangle2euler</code> (vector, theta)	Convert axis, angle pair to Euler angles
<code>euler2axangle</code> (z, y, x)	Return angle, axis corresponding to these Euler angles
<code>euler2mat</code> (z, y, x)	Return matrix for rotations around z, y and x axes
<code>euler2quat</code> (z, y, x)	Return quaternion corresponding to these Euler angles
<code>mat2euler</code> (M[, cy_thresh])	Discover Euler angle vector from 3x3 matrix
<code>quat2euler</code> (q)	Return Euler angles corresponding to quaternion <i>q</i>

### 4.11.1 axangle2euler

`transforms3d.taitbryan.axangle2euler`(*vector*, *theta*)

Convert axis, angle pair to Euler angles

#### Parameters

##### **vector**

[3 element sequence] vector specifying axis for rotation.

##### **theta**

[scalar] angle of rotation

#### Returns

##### **z**

[scalar]

##### **y**

[scalar]

##### **x**

[scalar] Rotations in radians around z, y, x axes, respectively

#### Notes

It's possible to reduce the amount of calculation a little, by combining parts of the `angle_axis2mat` and `mat2euler` functions, but the reduction in computation is small, and the code repetition is large.

#### Examples

```
>>> z, y, x = axangle2euler([1, 0, 0], 0)
>>> np.allclose((z, y, x), 0)
True
```

### 4.11.2 euler2axangle

`transforms3d.taitbryan.euler2axangle`(*z*, *y*, *x*)

Return angle, axis corresponding to these Euler angles

Uses the z, then y, then x convention above

**Parameters**

- z**  
[scalar] Rotation angle in radians around z-axis (performed first)
- y**  
[scalar] Rotation angle in radians around y-axis
- x**  
[scalar] Rotation angle in radians around x-axis (performed last)

**Returns**

- vector**  
[array shape (3,)] axis around which rotation occurs
- theta**  
[scalar] angle of rotation

**Examples**

```
>>> vec, theta = euler2axangle(0, 1.5, 0)
>>> np.allclose(vec, [0, 1, 0])
True
>>> theta
1.5
```

### 4.11.3 euler2mat

`transforms3d.taitbryan.euler2mat(z, y, x)`

Return matrix for rotations around z, y and x axes

Uses the convention of static-frame rotation around the z, then y, then x axis.

**Parameters**

- z**  
[scalar] Rotation angle in radians around z-axis (performed first)
- y**  
[scalar] Rotation angle in radians around y-axis
- x**  
[scalar] Rotation angle in radians around x-axis (performed last)

**Returns**

- M**  
[array shape (3,3)] Rotation matrix giving same rotation as for given angles

**Notes**

The direction of rotation is given by the right-hand rule. Orient the thumb of the right hand along the axis around which the rotation occurs, with the end of the thumb at the positive end of the axis; curl your fingers; the direction your fingers curl is the direction of rotation. Therefore, the rotations are counterclockwise if looking along the axis of rotation from positive to negative.

## Examples

```
>>> zrot = 1.3 # radians
>>> yrot = -0.1
>>> xrot = 0.2
>>> M = euler2mat(zrot, yrot, xrot)
>>> M.shape == (3, 3)
True
```

The output rotation matrix is equal to the composition of the individual rotations

```
>>> M1 = euler2mat(zrot, 0, 0)
>>> M2 = euler2mat(0, yrot, 0)
>>> M3 = euler2mat(0, 0, xrot)
>>> composed_M = np.dot(M3, np.dot(M2, M1))
>>> np.allclose(M, composed_M)
True
```

When applying M to a vector, the vector should column vector to the right of M. If the right hand side is a 2D array rather than a vector, then each column of the 2D array represents a vector.

```
>>> vec = np.array([1, 0, 0]).reshape((3,1))
>>> v2 = np.dot(M, vec)
>>> vecs = np.array([[1, 0, 0],[0, 1, 0]]).T # giving 3x2 array
>>> vecs2 = np.dot(M, vecs)
```

Rotations are counter-clockwise.

```
>>> zred = np.dot(euler2mat(np.pi/2, 0, 0), np.eye(3))
>>> np.allclose(zred, [[0, -1, 0],[1, 0, 0], [0, 0, 1]])
True
>>> yred = np.dot(euler2mat(0, np.pi/2, 0), np.eye(3))
>>> np.allclose(yred, [[0, 0, 1],[0, 1, 0], [-1, 0, 0]])
True
>>> xred = np.dot(euler2mat(0, 0, np.pi/2), np.eye(3))
>>> np.allclose(xred, [[1, 0, 0],[0, 0, -1], [0, 1, 0]])
True
```

### 4.11.4 euler2quat

`transforms3d.taitbryan.euler2quat(z, y, x)`

Return quaternion corresponding to these Euler angles

Uses the z, then y, then x convention above

#### Parameters

- z**  
[scalar] Rotation angle in radians around z-axis (performed first)
- y**  
[scalar] Rotation angle in radians around y-axis
- x**  
[scalar] Rotation angle in radians around x-axis (performed last)

#### Returns

### quat

[array shape (4,)] Quaternion in w, x, y z (real, then vector) format

### Notes

Formula from Sympy - see `eulerangles.py` in `derivations` subdirectory

## 4.11.5 mat2euler

`transforms3d.taitbryan.mat2euler(M, cy_thresh=None)`

Discover Euler angle vector from 3x3 matrix

Uses the conventions above.

### Parameters

#### M

[array-like, shape (3,3)]

#### cy\_thresh

[None or scalar, optional] threshold below which to give up on straightforward arctan for estimating x rotation. If None (default), estimate from precision of input.

### Returns

#### z

[scalar]

#### y

[scalar]

#### x

[scalar] Rotations in radians around z, y, x axes, respectively

### Notes

If there was no numerical error, the routine could be derived using Sympy expression for z then y then x rotation matrix, (see `eulerangles.py` in `derivations` subdirectory):

```
[
    cos(y)*cos(z),          -cos(y)*sin(z),
    ↪ sin(y)],
[cos(x)*sin(z) + cos(z)*sin(x)*sin(y), cos(x)*cos(z) - sin(x)*sin(y)*sin(z), -
    ↪ cos(y)*sin(x)],
[sin(x)*sin(z) - cos(x)*cos(z)*sin(y), cos(z)*sin(x) + cos(x)*sin(y)*sin(z), ↪
    ↪ cos(x)*cos(y)]
```

This gives the following solutions for [z, y, x]:

```
z = atan2(-r12, r11)
y = asin(r13)
x = atan2(-r23, r33)
```

Problems arise when  $\cos(y)$  is close to zero, because both of:

```
z = atan2(cos(y)*sin(z), cos(y)*cos(z))
x = atan2(cos(y)*sin(x), cos(x)*cos(y))
```

will be close to  $\text{atan2}(0, 0)$ , and highly unstable.

The `cy` fix for numerical instability in this code is from: *Euler Angle Conversion* by Ken Shoemake, p222-9 ; in: *Graphics Gems IV*, Paul Heckbert (editor), Academic Press, 1994, ISBN: 0123361559. Specifically it comes from `EulerAngles.c` and deals with the case where  $\cos(y)$  is close to zero:

- <http://www.graphicsgems.org/>
- [https://github.com/erich666/GraphicsGems/blob/master/gemsiv/euler\\_angle/EulerAngles.c#L68](https://github.com/erich666/GraphicsGems/blob/master/gemsiv/euler_angle/EulerAngles.c#L68)

The code appears to be licensed (from the website) as “can be used without restrictions”.

### 4.11.6 quat2euler

`transforms3d.taitbryan.quat2euler(q)`

Return Euler angles corresponding to quaternion  $q$

#### Parameters

**q**  
[4 element sequence] w, x, y, z of quaternion

#### Returns

**z**  
[scalar] Rotation angle in radians around z-axis (performed first)

**y**  
[scalar] Rotation angle in radians around y-axis

**x**  
[scalar] Rotation angle in radians around x-axis (performed last)

#### Notes

It’s possible to reduce the amount of calculation a little, by combining parts of the `quat2mat` and `mat2euler` functions, but the reduction in computation is small, and the code repetition is large.

## 4.12 utils

Utilities for transforms3d

<code>inique(iterable)</code>	Generate unique elements from <i>iterable</i>
<code>normalized_vector(vec)</code>	Return vector divided by Euclidean (L2) norm
<code>permuted_signs(seq)</code>	Generate permuted signs for sequence <i>seq</i>
<code>permuted_with_signs(seq)</code>	Return all permutations of <i>seq</i> with all sign permutations
<code>random_unit_vector(rng)</code>	Return random normalized 3D unit vector
<code>vector_norm(vec)</code>	Return vector Euclidean (L2) norm

### 4.12.1 inique

`transforms3d.utils.inique(iterable)`

Generate unique elements from *iterable*

#### Parameters

**iterable**  
[iterable]

#### Returns

**gen**[generator] generator that yields unique elements from *iterable***Examples**

```
>>> tuple(unique([0, 1, 2, 0, 2, 3]))
(0, 1, 2, 3)
```

### 4.12.2 normalized\_vector

`transforms3d.utils.normalized_vector(vec)`

Return vector divided by Euclidean (L2) norm

See *unit vector* and *Euclidean norm***Parameters****vec**

[array-like shape (3,)]

**Returns****nvec**

[array shape (3,)] vector divided by L2 norm

**Examples**

```
>>> vec = [1, 2, 3]
>>> l2n = np.sqrt(np.dot(vec, vec))
>>> nvec = normalized_vector(vec)
>>> np.allclose(np.array(vec) / l2n, nvec)
True
>>> vec = np.array([[1, 2, 3]])
>>> vec.shape
(1, 3)
>>> normalized_vector(vec).shape
(3,)
```

### 4.12.3 permuted\_signs

`transforms3d.utils.permuted_signs(seq)`Generate permuted signs for sequence *seq***Parameters****seq**

[sequence]

**Returns****gen**[generator] generator returning *seq* with signs permuted

### Examples

```
>>> tuple(permuted_signs([1, -2, 0]))
((1, -2, 0), (1, -2, 0), (1, 2, 0), (1, 2, 0), (-1, -2, 0), (-1, -2, 0), (-1, 2, 0),
 → (-1, 2, 0))
```

#### 4.12.4 permuted\_with\_signs

transforms3d.utils.**permuted\_with\_signs**(seq)

Return all permutations of *seq* with all sign permutations

##### Parameters

**seq**  
[sequence]

##### Returns

**gen**  
[generator] generator returning permutations and sign permutations

### Examples

```
>>> tuple(permuted_with_signs((1,2)))
((1, 2), (1, -2), (-1, 2), (-1, -2), (2, 1), (2, -1), (-2, 1), (-2, -1))
```

#### 4.12.5 random\_unit\_vector

transforms3d.utils.**random\_unit\_vector**(rng=None)

Return random normalized 3D unit vector

##### Parameters

**rng**  
[None or random number generator, optional] *rng* must have function / method *normal* that allows *size=* keyword.

##### Returns

**vec**  
[shape (3,) array] Vector at random on unit sphere.

### Notes

<https://mathworld.wolfram.com/SpherePointPicking.html>

#### 4.12.6 vector\_norm

transforms3d.utils.**vector\_norm**(vec)

Return vector Euclidean (L2) norm

See *unit vector* and *Euclidean norm*

##### Parameters

**vec**  
[array-like shape (3,)]

##### Returns

**norm**  
[scalar]

### Examples

```
>>> vec = [1, 2, 3]
>>> l2n = np.sqrt(np.dot(vec, vec))
>>> nvec = vector_norm(vec)
>>> np.allclose(nvec, np.sqrt(np.dot(vec, vec)))
True
```

## 4.13 zooms

Functions for working with zooms (scales)

Terms used in function names:

- *mat* : array shape (3, 3) (3D non-homogenous coordinates)
- *aff* : affine array shape (4, 4) (3D homogenous coordinates)
- *zfdir* : zooms encoded by factor scalar and direction vector

<code>aff2zfdir(aff)</code>	Return scaling factor, direction and origin from scaling matrix.
<code>mat2zfdir(mat)</code>	Return scaling factor and direction from zoom (scaling) matrix
<code>zfdir2aff(factor[, direction, origin])</code>	Return affine to scale by <i>factor</i> around <i>origin</i> in <i>direction</i> .
<code>zfdir2mat(factor[, direction])</code>	Return matrix to scale by factor around origin in direction.

### 4.13.1 aff2zfdir

`transforms3d.zooms.aff2zfdir(aff)`

Return scaling factor, direction and origin from scaling matrix.

#### Parameters

**aff**  
[array-like shape (4,4)] 4x4 *affine transformation* matrix.

#### Returns

**factor**  
[scalar] zoom (scale) factor as for `zfdir2mat`

**direction**  
[None or array, shape (3,)] direction of zoom as for `zfdir2mat`. None if scaling is uniform.

**origin**  
[array, shape (3,)] origin of zooms



## Examples

```
>>> factor = np.random.random() * 10 - 5
>>> direct = np.random.random(3) - 0.5
>>> origin = np.random.random(3) - 0.5
>>> S0 = zfdir2aff(factor)
>>> f2, d2, o2 = aff2zfdir(S0)
>>> np.allclose(S0, zfdir2aff(f2, d2, o2))
True
>>> S0 = zfdir2aff(factor, direct)
>>> f2, d2, o2 = aff2zfdir(S0)
>>> np.allclose(S0, zfdir2aff(f2, d2, o2))
True
>>> S0 = zfdir2aff(factor, direct, origin)
```

### 4.13.2 mat2zfdir

transforms3d.zooms.**mat2zfdir**(*mat*)

Return scaling factor and direction from zoom (scaling) matrix

#### Parameters

**mat**

[array-like shape (3,3)] 3x3 zoom matrix

#### Returns

**factor**

[scalar] zoom (scale) factor as for zfdir2mat

**direction**

[None or array, shape (3,)] direction of zoom as for zfdir2mat. None if scaling is uniform.

## Examples

Roundtrip may not generate same factor, direction, but the generated transformation matrices will be the same

```
>>> factor = np.random.random() * 10 - 5
>>> S0 = zfdir2mat(factor, None)
>>> f2, d2 = mat2zfdir(S0)
>>> S1 = zfdir2mat(f2, d2)
>>> np.allclose(S0, S1)
True
>>> direct = np.random.random(3) - 0.5
>>> S0 = zfdir2mat(factor, direct)
>>> f2, d2 = mat2zfdir(S0)
>>> S1 = zfdir2mat(f2, d2)
>>> np.allclose(S0, S1)
True
```

### 4.13.3 zfdir2aff

transforms3d.zooms.**zfdir2aff**(*factor*, *direction=None*, *origin=None*)

Return affine to scale by *factor* around *origin* in *direction*.

Use factor -1 for point symmetry.

**Parameters****factor**

[scalar] factor to zoom by (see *direction*)

**direction**

[None or array-like shape (3,)] If None, simply apply uniform scaling by *factor*. Otherwise, apply scaling along direction given by vector *direction*. We convert direction to a *unit vector* before application.

**origin**

[None or array-like shape (3,)] point at which to apply implied zooms

**Returns****aff**

[array shape (4,4)] 4x4 transformation matrix implementing zooms

**Examples**

```
>>> v = (np.random.rand(3, 5) - 0.5) * 20.0
>>> S = zfdir2aff(-1.234)[:3,:3]
>>> np.allclose(np.dot(S, v), -1.234*v)
True
>>> factor = np.random.random() * 10 - 5
>>> direct = np.random.random(3) - 0.5
>>> origin = np.random.random(3) - 0.5
>>> S = zfdir2aff(factor, None, origin)
>>> S = zfdir2aff(factor, direct, origin)
```

### 4.13.4 zfdir2mat

transforms3d.zooms.**zfdir2mat**(*factor*, *direction=None*)

Return matrix to scale by factor around origin in direction.

Use factor == -1 for point symmetry.

**Parameters****factor**

[scalar] factor to zoom by (see *direction*)

**direction**

[None or array-like shape (3,), optional] If None, simply apply uniform scaling by *factor*. Otherwise, apply scaling along direction given by vector *direction*. We convert direction to a *unit vector* before application.

**Returns****mat**

[array shape (3,3)] 3x3 transformation matrix implementing zooms

**Examples**

```
>>> v = (np.random.rand(3, 5) - 0.5) * 20.0
>>> S = zfdir2mat(-1.234)
>>> np.allclose(np.dot(S, v), -1.234*v)
True
```

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```
>>> factor = np.random.random() * 10 - 5
>>> direct = np.random.random(3) - 0.5
>>> S = zfdi2mat(factor, direct)
```



## GLOSSARY

**Affine matrix**

A matrix implementing an *affine transformation* in *homogenous coordinates*. For a 3 dimensional transform, the matrix is shape 4 by 4.

**Affine transformation**

See [wikipedia affine](#) definition. An affine transformation is a *linear transformation* followed by a translation.

**Axis angle**

A representation of rotation. See: [wikipedia axis angle](#) . From Euler's rotation theorem we know that any rotation or sequence of rotations can be represented by a single rotation about an axis. The axis  $\hat{u}$  is a *unit vector*. The angle is  $\theta$ . The *rotation vector* is a more compact representation of  $\theta$  and  $\hat{u}$ .

**Euclidean norm**

Also called Euclidean length, or L2 norm. The Euclidean norm  $\|\mathbf{x}\|$  of a vector  $\mathbf{x}$  is given by:

$$\|\mathbf{x}\| := \sqrt{x_1^2 + \cdots + x_n^2}$$

Pure Pythagoras.

**Euler angles**

See: [wikipedia Euler angles](#) and [Mathworld Euler angles](#).

**Gimbal lock**

See *Gimbal lock*

**Homogenous coordinates**

See [wikipedia homogenous coordinates](#)

**Linear transformation**

A linear transformation is one that preserves lines - that is, if any three points are on a line before transformation, they are also on a line after transformation. See [wikipedia linear transform](#). Rotation, scaling and shear are linear transformations.

**Quaternion**

See: [wikipedia quaternion](#). An extension of the complex numbers that can represent a rotation. Quaternions have 4 values,  $w, x, y, z$ .  $w$  is the *real* part of the quaternion and the vector  $x, y, z$  is the *vector* part of the quaternion. Quaternions are less intuitive to visualize than *Euler angles* but do not suffer from *gimbal lock* and are often used for rapid interpolation of rotations.

**Reflection**

A transformation that can be thought of as transforming an object to its mirror image. The mirror in the transformation is a plane. A plan can be defined with a point and a vector normal to the plane. See [wikipedia reflection](#).

**Rotation matrix**

See [wikipedia rotation matrix](#). A rotation matrix is a matrix implementing a rotation. Rotation matrices are square and orthogonal. That means, that the rotation matrix  $R$  has columns and rows that are *unit vector*, and

where  $R^T R = I$  ( $R^T$  is the transpose and  $I$  is the identity matrix). Therefore  $R^T = R^{-1}$  ( $R^{-1}$  is the inverse). Rotation matrices also have a determinant of 1.

#### Rotation vector

A representation of an *axis angle* rotation. The angle  $\theta$  and unit vector axis  $\hat{u}$  are stored in a *rotation vector*  $\mathbf{u}$ , such that:

$$\theta = \|\mathbf{u}\|$$

$$\hat{u} = \frac{\mathbf{u}}{\|\mathbf{u}\|}$$

where  $\|\mathbf{u}\|$  is the *Euclidean norm* of  $\mathbf{u}$

#### Shear matrix

Square matrix that results in shearing transforms - see [wikipedia shear matrix](#).

#### Unit vector

A vector  $\hat{u}$  with a *Euclidean norm* of 1. Normalized vector is a synonym. The “hat” over the  $\hat{u}$  is a convention to express the fact that it is a unit vector.

## GUIDE TO MAKING A TRANSFORMS3D RELEASE

A guide for developers who are doing a Transforms3d release

### 6.1 Release checklist

- Review the open list of [transforms3d issues](#). Check whether there are outstanding issues that can be closed, and whether there are any issues that should delay the release. Label them !
- Review and update the release notes. Review and update the Changelog file. Get a partial list of contributors with something like:

```
git shortlog -ns 0.6.0..
```

where 0.6.0 was the last release tag name.

Then manually go over `git shortlog 0.6.0..` to make sure the release notes are as complete as possible and that every contributor was recognized.

- Use the opportunity to update the .mailmap file if there are any duplicate authors listed from `git shortlog -ns`.
- Add any new authors to the AUTHORS file. Add any new entries to the THANKS file.
- Check the copyright years in doc/conf.py and LICENSE
- Clean:

```
git clean -fxd
```

- Run tests after installing into a virtualenv, to test that installing works correctly:

```
mkvirtualenv transforms3d-test
pip install pytest wheel
git clean -fxd
python setup.py install
mkdir for_test
cd for_test
pytest --doctest-modules transforms3d
```

- Make sure all tests pass on your local machine (from the Transforms3d root directory):

```
pytest --doctest-modules transforms3d
```

- Check the documentation Doctests:

```
pip install -r doc-requirements.txt
cd doc
make doctest
cd ..
```

- The release should now be ready.

## 6.2 Doing the release

You might want to make tag the release commit on your local machine, push to [pypi](#), review, fix, rebase, until all is good. Then and only then do you push to upstream on github.

- Make a signed annotated tag for the release with tag of form 0.6.0:

```
git tag -sm 'Fifth public release' 0.6.0
```

Because we're using [versioneer](#) it is the tag which sets the package version.

- Once everything looks good, upload the source release to PyPi:

```
pip install build twine
git clean -fxd
python -m build . --sdist
twine upload -s dist/transforms*.gz
```

- Remember you'll need your `~/.pypirc` file set up right for this to work. See [setuptools intro](#). If you have 2-factor authentication, the file may look something like this:

```
[pypi]
username = __token__
```

- Check how everything looks on Pypi - the description, the packages. If necessary delete the release and try again if it doesn't look right.
- Push the tag with `git push --tags`
- Upload the docs with:

```
pip install -e . # if you haven't done this already
pip install -r doc-requirements.txt
cd doc
make github
```

- Announce to the mailing lists. With fear and trembling.



## REFACTORING PLAN

Note the *Naming conventions*.

Base the module distinctions on the naming conventions.

In general, routines that create or break down affines, rather than, say 3x3 matrices, go with the - say - 3x3 routines, and are named `aff2something`, `something2aff`.

Routines that only apply to affines, like `compose`, `decompose`, go into the `affines` module.

Different decompositions might have different names - such as `decompose_szrt`, returning transformations in order that they are performed - here shears, zooms, rotations, translations.

Move the SPM (ND affine) `decompose` to `decompose_szrt_nd`.

Maybe move the comments from Euler code out into doc tree.

### 7.1 To integrate

- `projection_matrix`, `projection_from_matrix`: move to own module, rename to `projpn2aff`. `aff2projpn`.
- `clip_matrix`: move to own module, rename to `clip2aff`
- `decompose_matrix`, `compose_matrix`: move to `affines` module, rename to `decompose_zsrt`, `compose_zsrt`
- `orthogonalization_matrix`: move to `misc` module, rename to `orth_aff`
- `superimposition_matrix`: move to `misc` module, rename to `vecs2aff`
- `quaternion_about_axis`, `quaternion_matrix`, `quaternion_from_matrix`, `quaternion_multiply`, `quaternion_conjugate`, `quaternion_inverse`: check against my code
- `quaternion_real`, `quaternion_imag`: needed?
- `quaternion_slerp`, `random_quaternion`: move to `quaternions` module, rename `qslerp`, `rand_quat`.
- `random_rotation_matrix`: move to some module as `rand_rmat`
- `Arcball` class, `arcball_map_to_sphere`, `arcball_constrain_to_axis`, `arcball_nearest_axis`: to own module
- `vector_norm`: move to `utils` module, review use after refactoring
- `unit_vector`: replace with `utils.normalized_vector`
- `random_vector`, `inverse_matrix`, `concatenate_matrices`: not obviously used, very simple code, remove?
- `_import_module`: for preferring C functions. Move to `utils` for now, consider C / python coexistence strategy.

## 7.2 C / python integration

See scipy.spatial - parallel C and Python routines, but there in a very simple case.

How about:

1. Import all the Python names via the `__init__.py`
2. Import all the C names (after renaming with agreed scheme as above or differently) into a `c.py __init__`-like module. Thus something like:

```
>>> import transforms3d as t3d
>>> M = t3d.euler3rmat(0.1, 0.3, 0.2)
```

for the python code, and:

```
>>> import transforms3d.c as t3dc
>>> M = t3dc.euler2mat(0.1, 0.3, 0.2)
```

for the C code? Or the other way round of course:

```
>>> import transforms3d as t3d
>>> import transforms3d.python as t3dpy
```

or both, and switch the `__init__` to import from the C or Python namespace with a one-liner.

## 7.3 Questions for Christoph

Does this refactoring plan make sense?

Does the naming scheme make sense (drawing distinction for example between 3x3 rotation matrix and affine)?

Now about the naming scheme for `compose` - e.g `compose_szrtp`?

OK to return a 3x3 rotation matrix from `decompose` rather than Euler angles?

How to classify `clip_matrix`, `orthogonalization_matrix`, `superimposition_matrix`?

OK to remove: `quaternion_real`, `quaternion_imag`, `random_vector`, `inverse_matrix`, `concatenate_matrices`?

What do you think of the C / Python scheme (it's about the same as your current one)?

How do you see the relationship between your current code and this code?

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