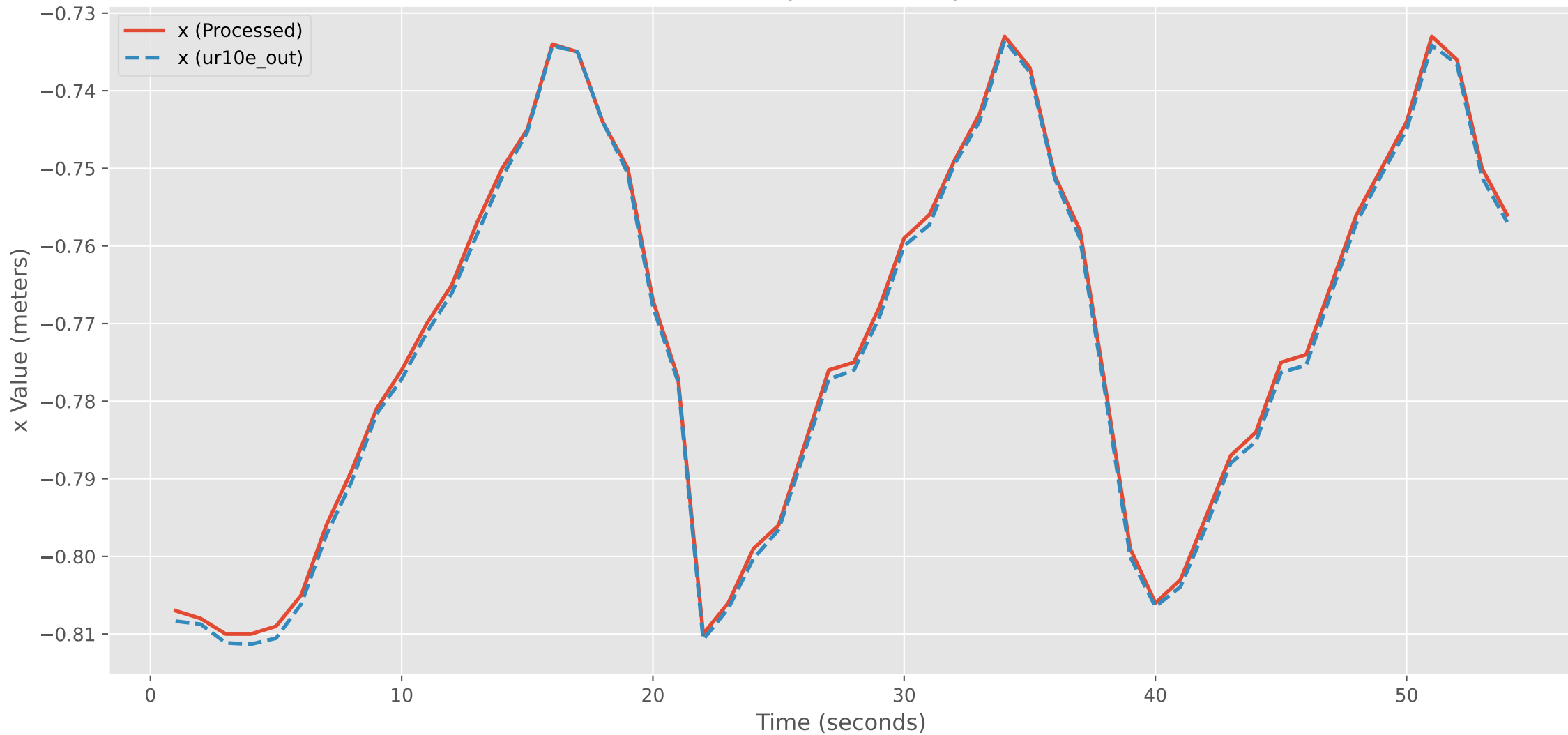
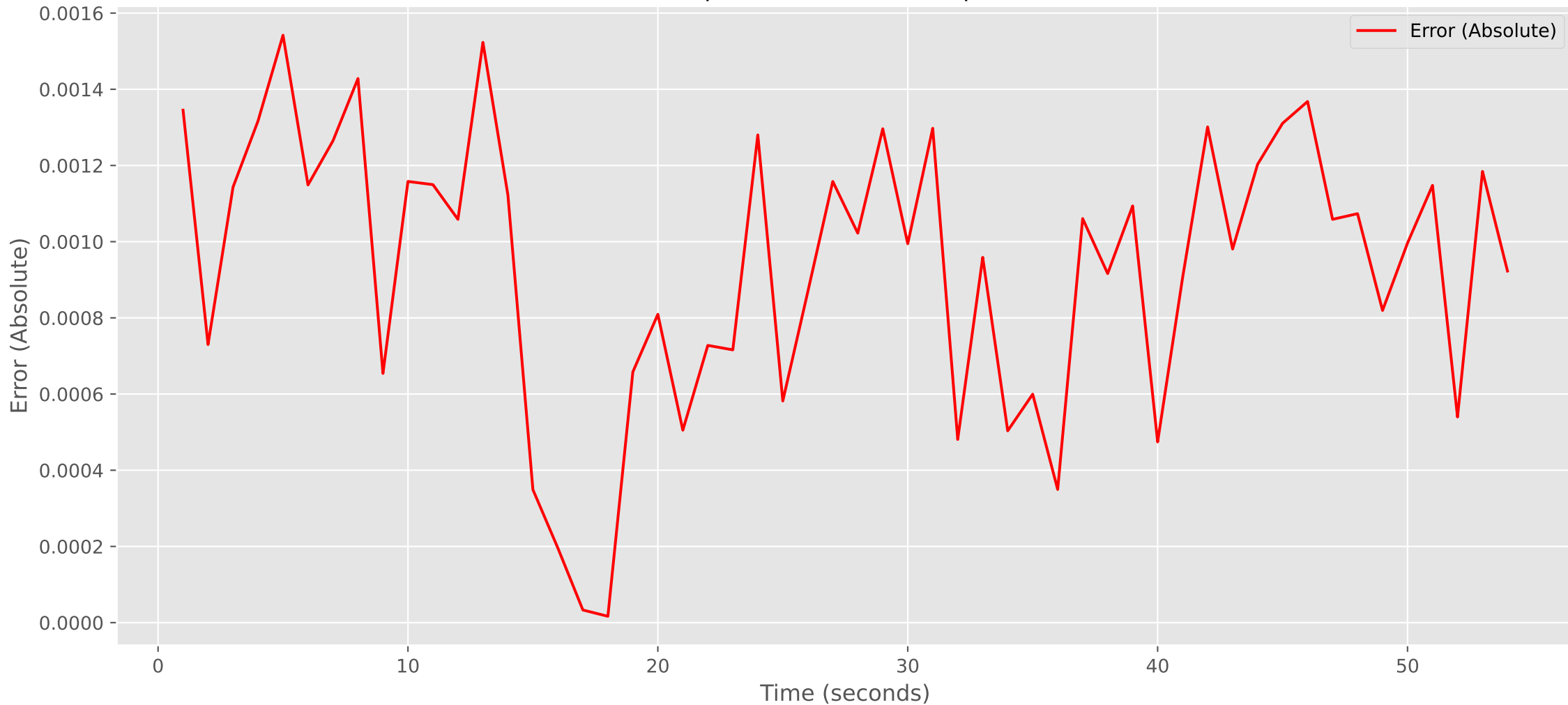


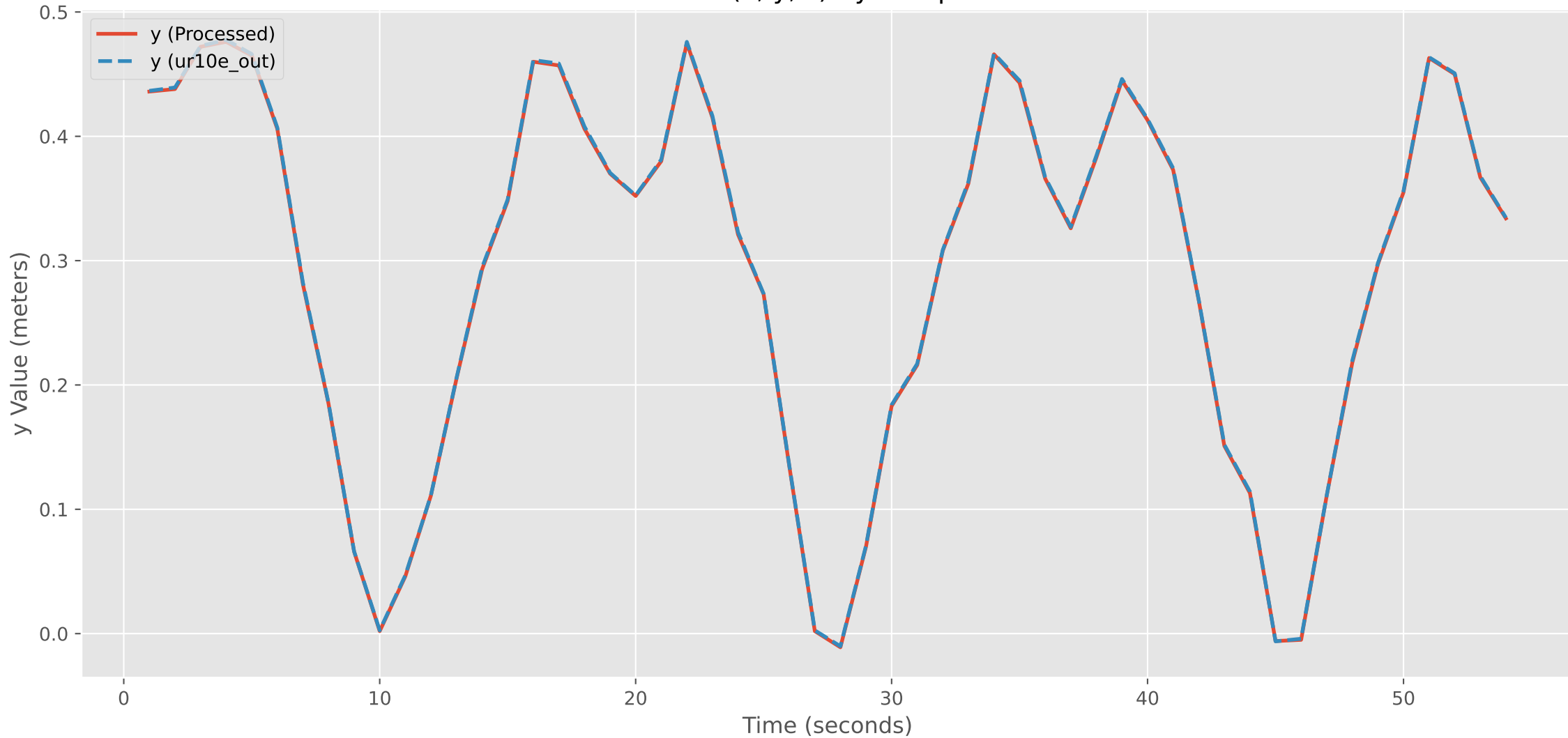
Position (x, y, z) - x Comparison



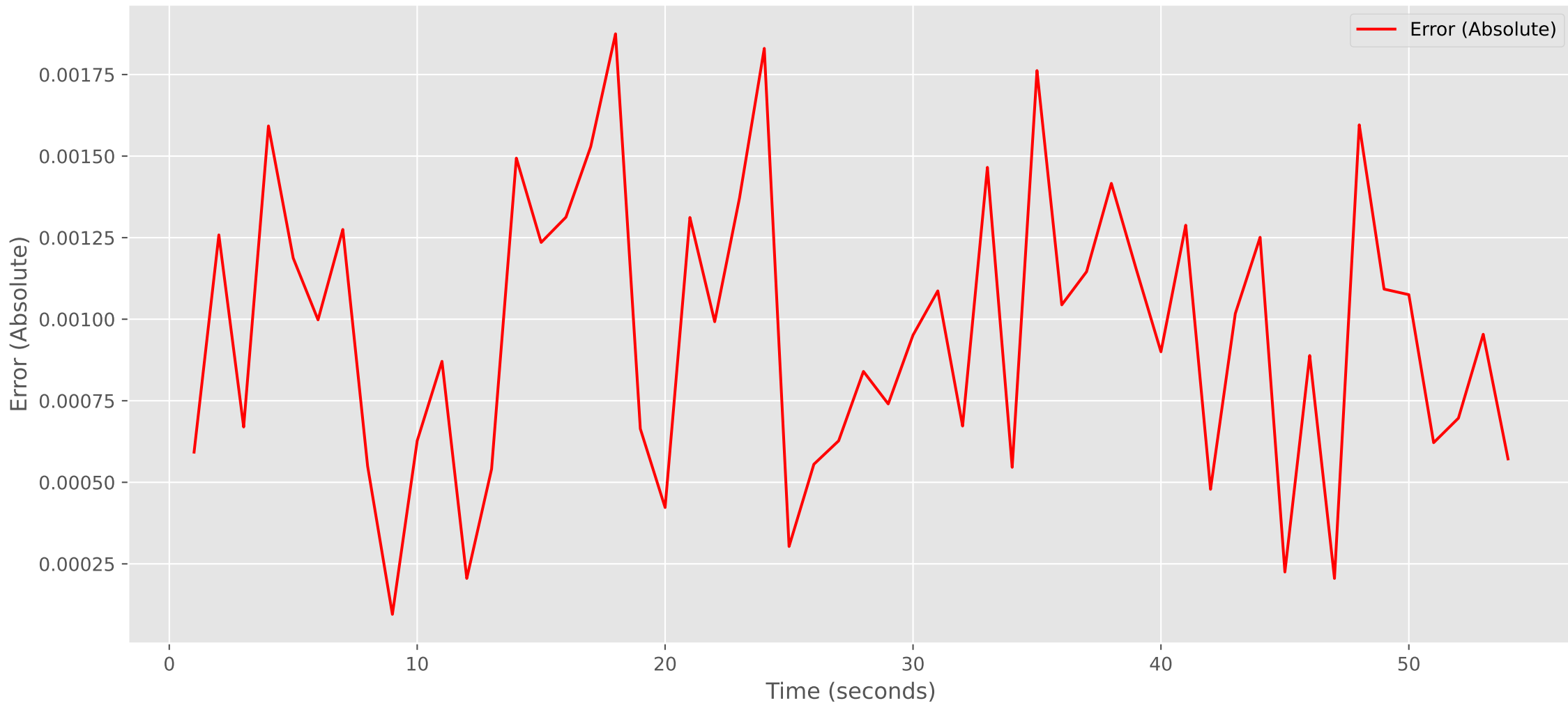
Position (x, y, z) - x Error
MAE: 0.0009 | Max Error: 0.0015 | RMSE: 0.0010



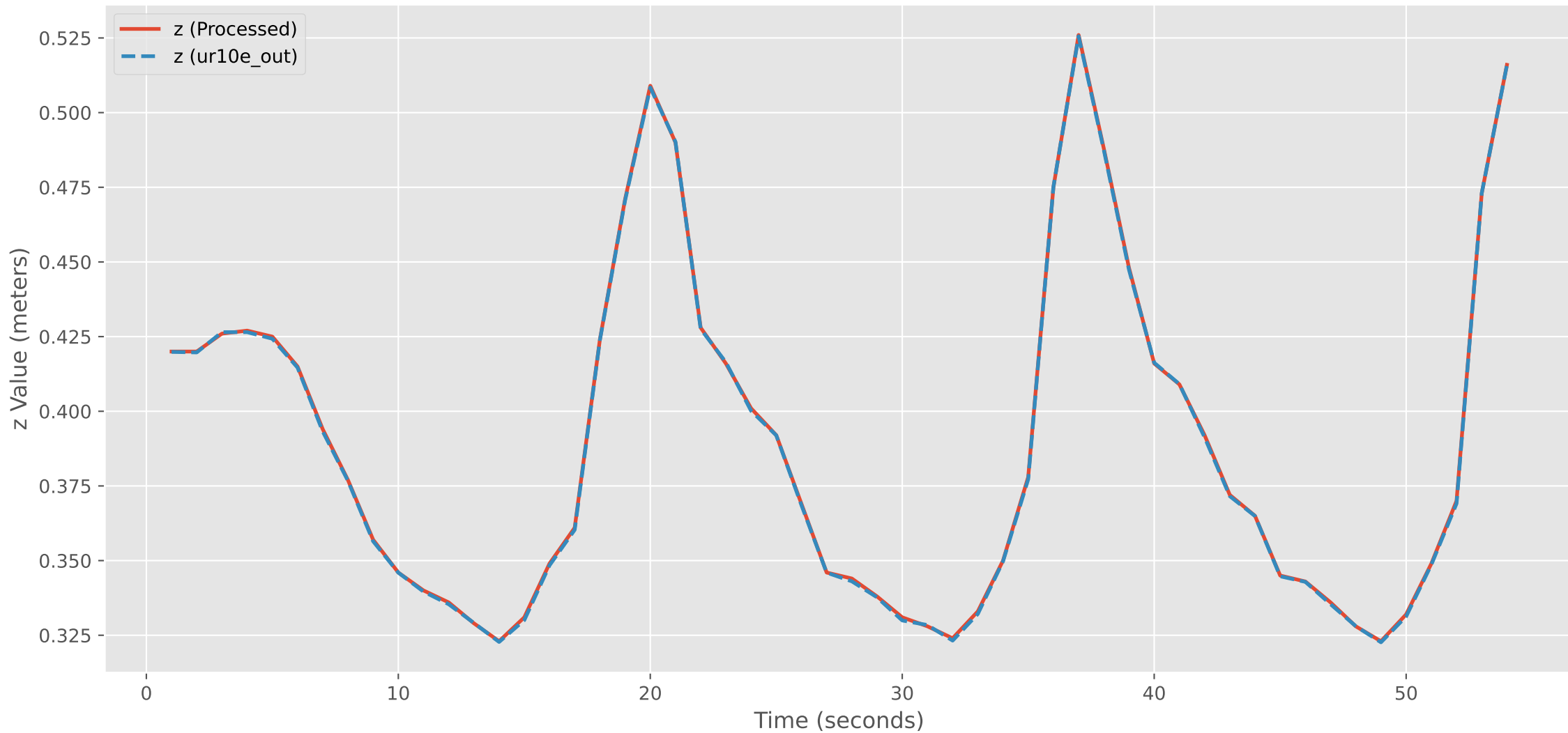
Position (x, y, z) - y Comparison



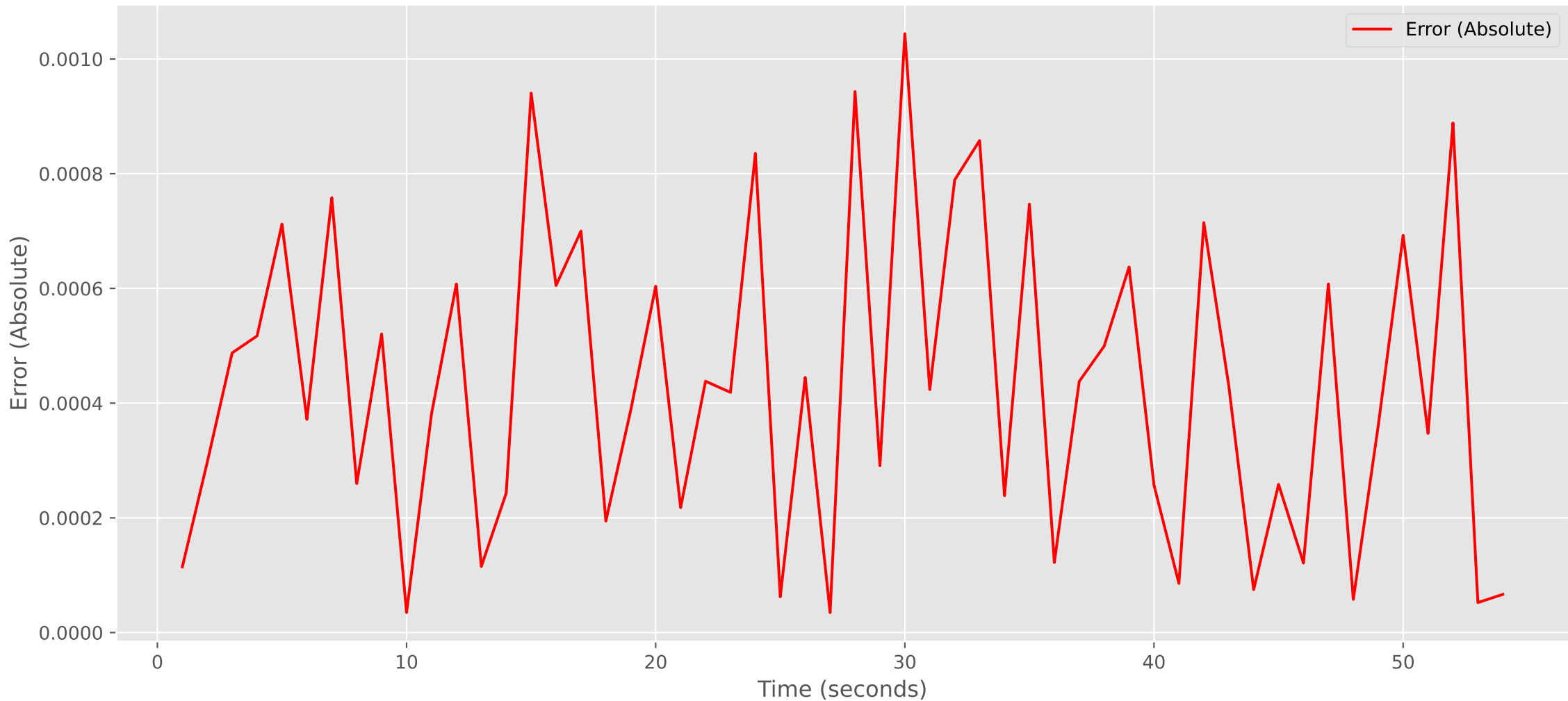
Position (x, y, z) - y Error
MAE: 0.0010 | Max Error: 0.0019 | RMSE: 0.0011



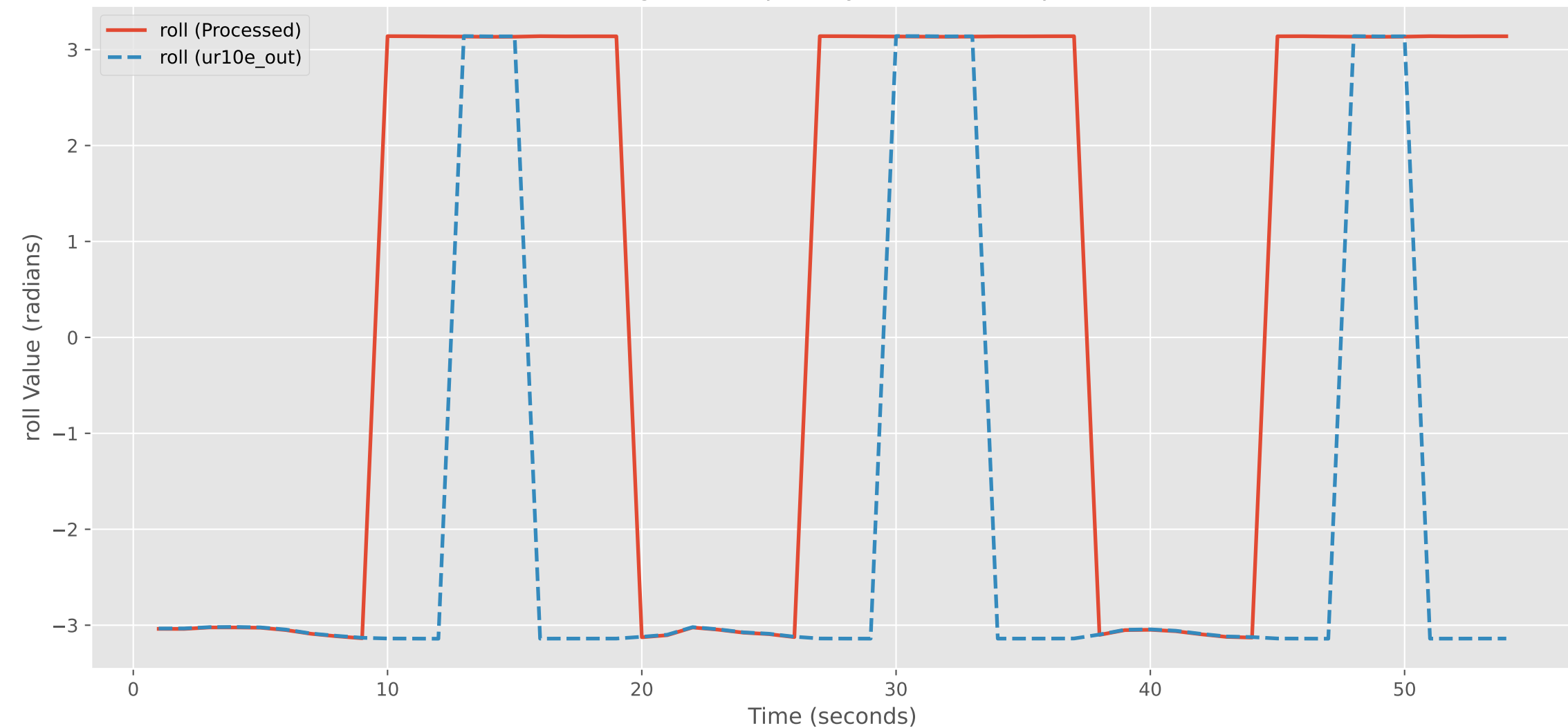
Position (x, y, z) - z Comparison



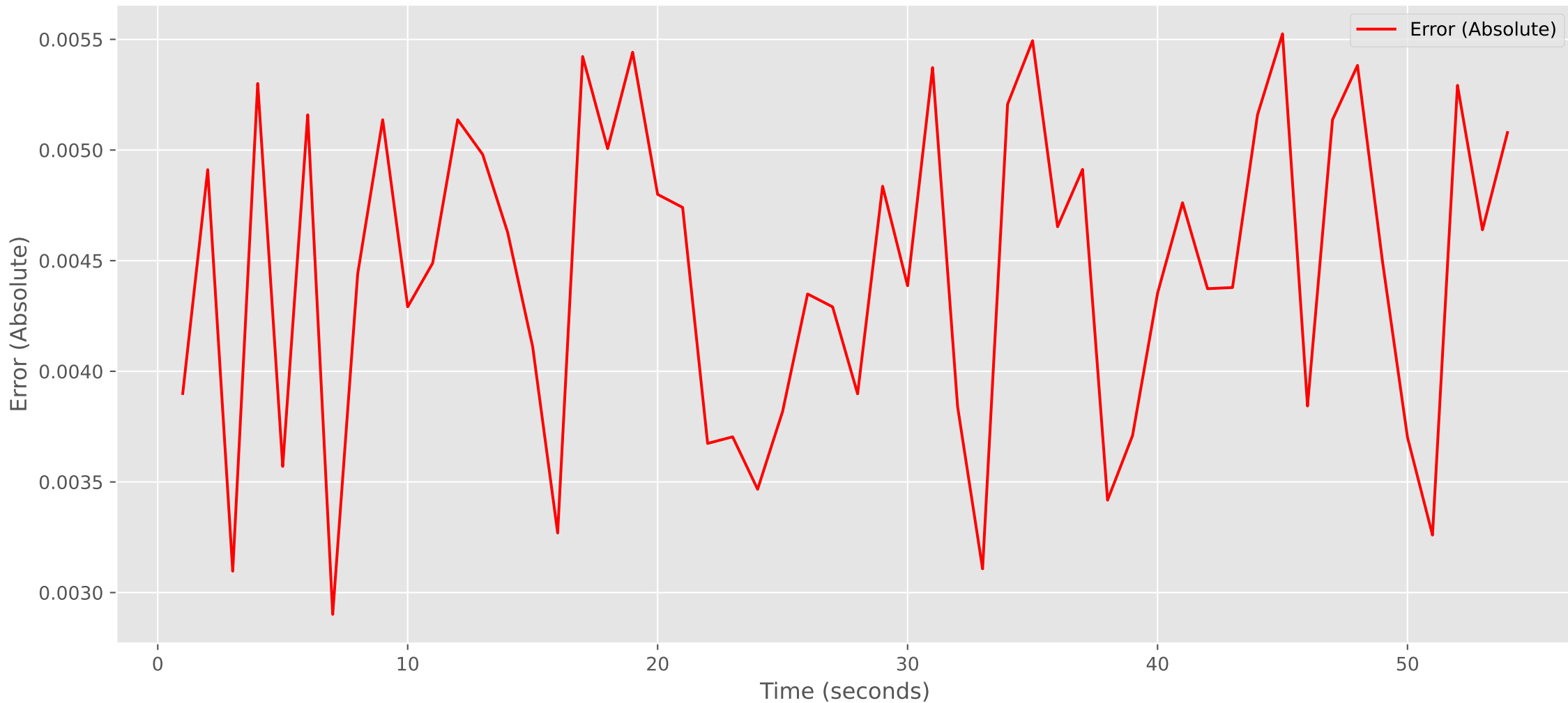
Position (x, y, z) - z Error
MAE: 0.0004 | Max Error: 0.0010 | RMSE: 0.0005



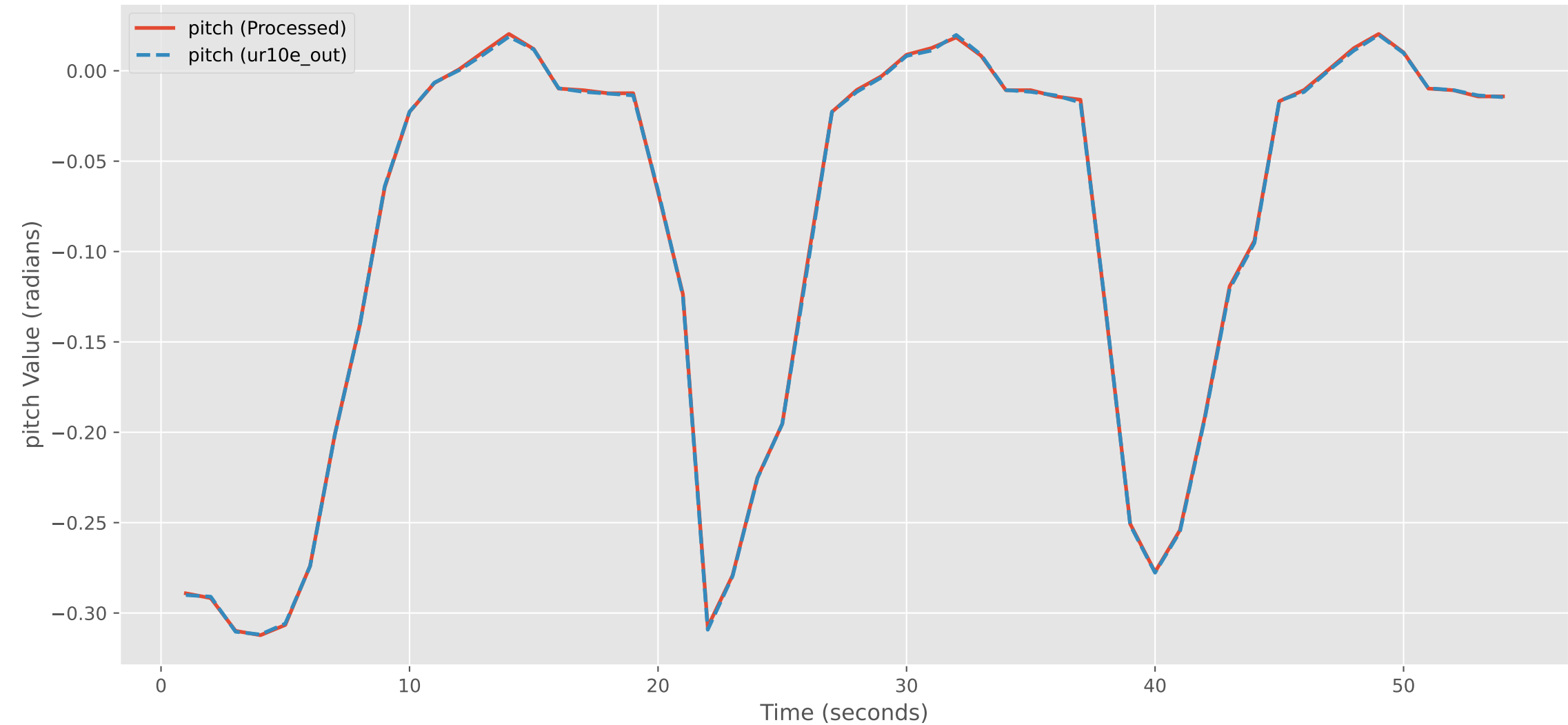
Euler Angles (roll, pitch, yaw) - roll Comparison



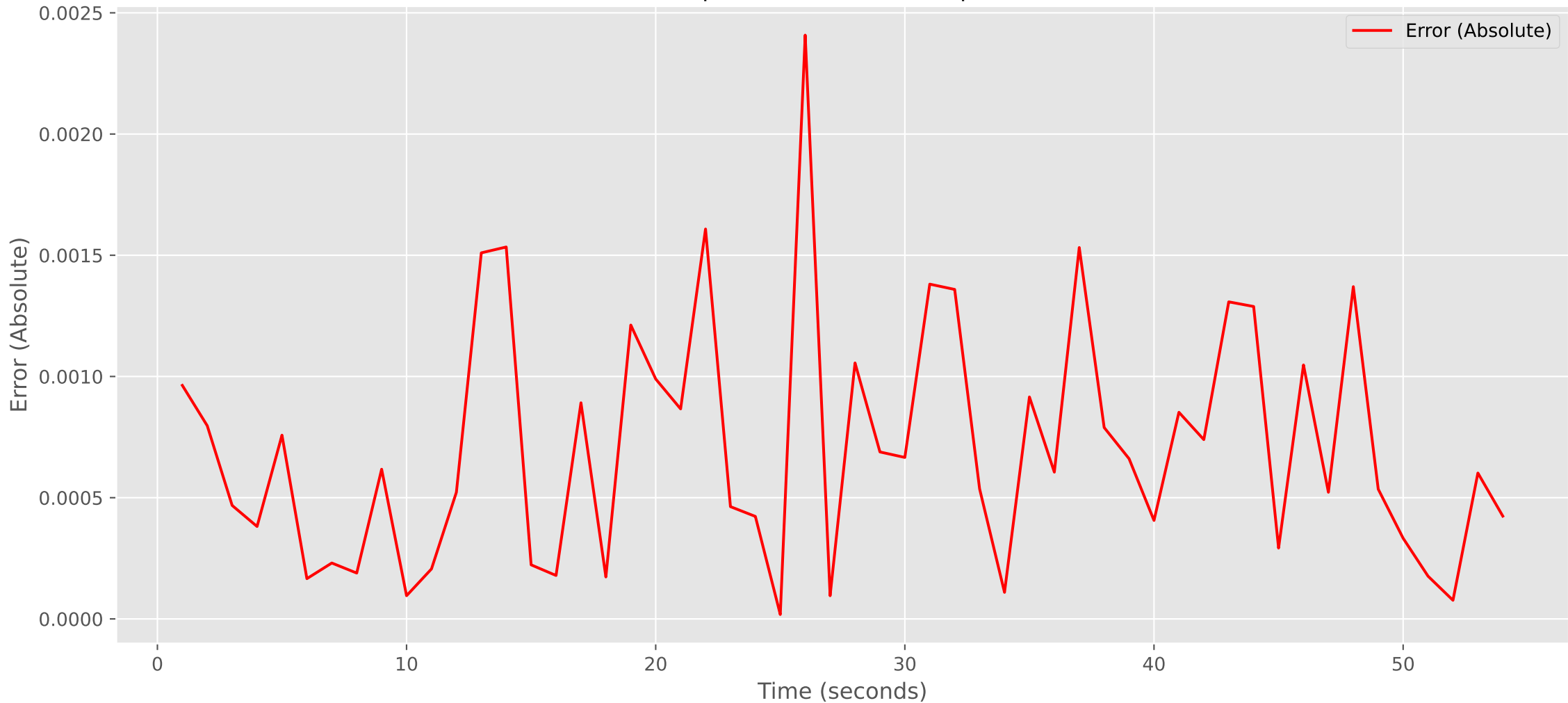
Euler Angles (roll, pitch, yaw) - roll Error
MAE: 0.0044 | Max Error: 0.0055 | RMSE: 0.0045



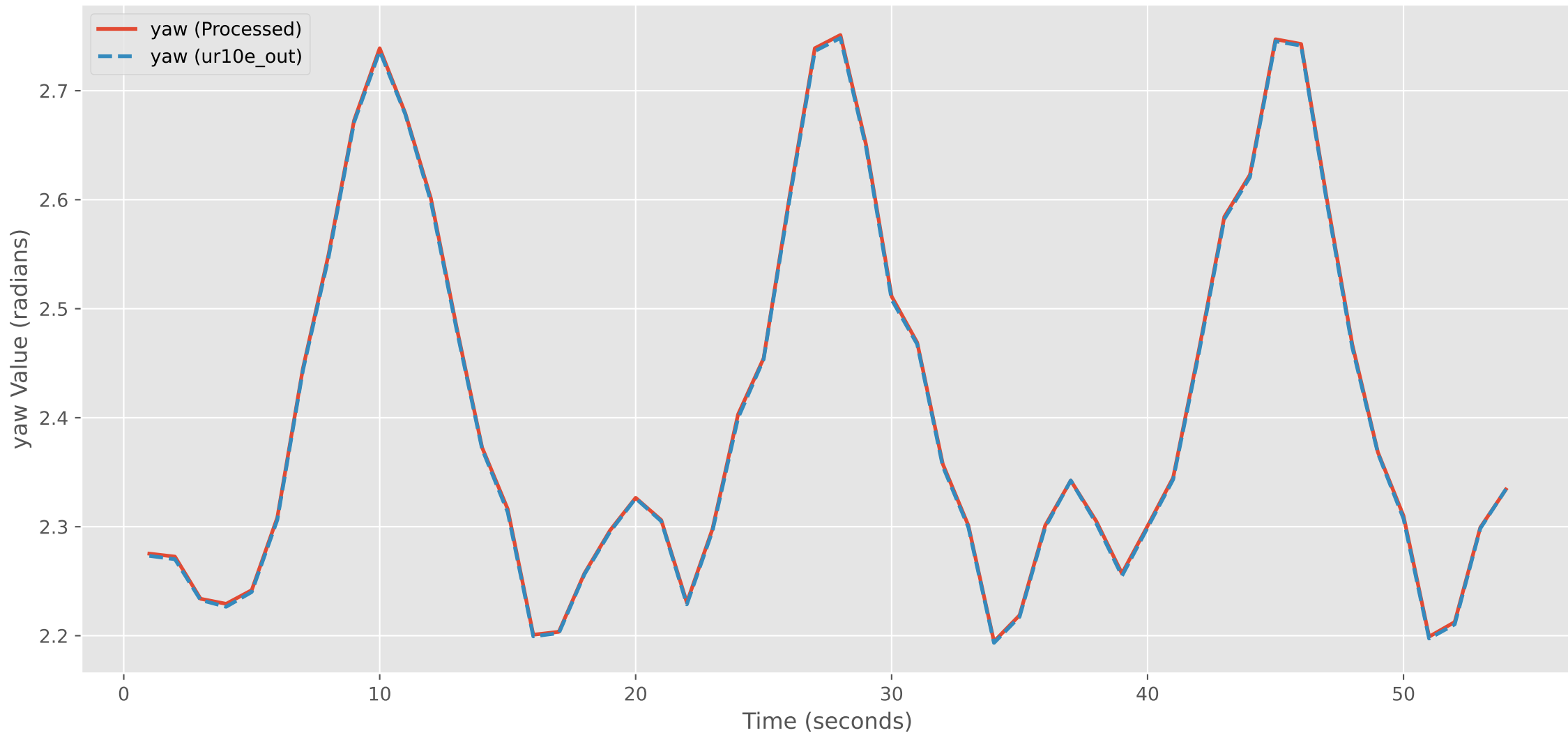
Euler Angles (roll, pitch, yaw) - pitch Comparison



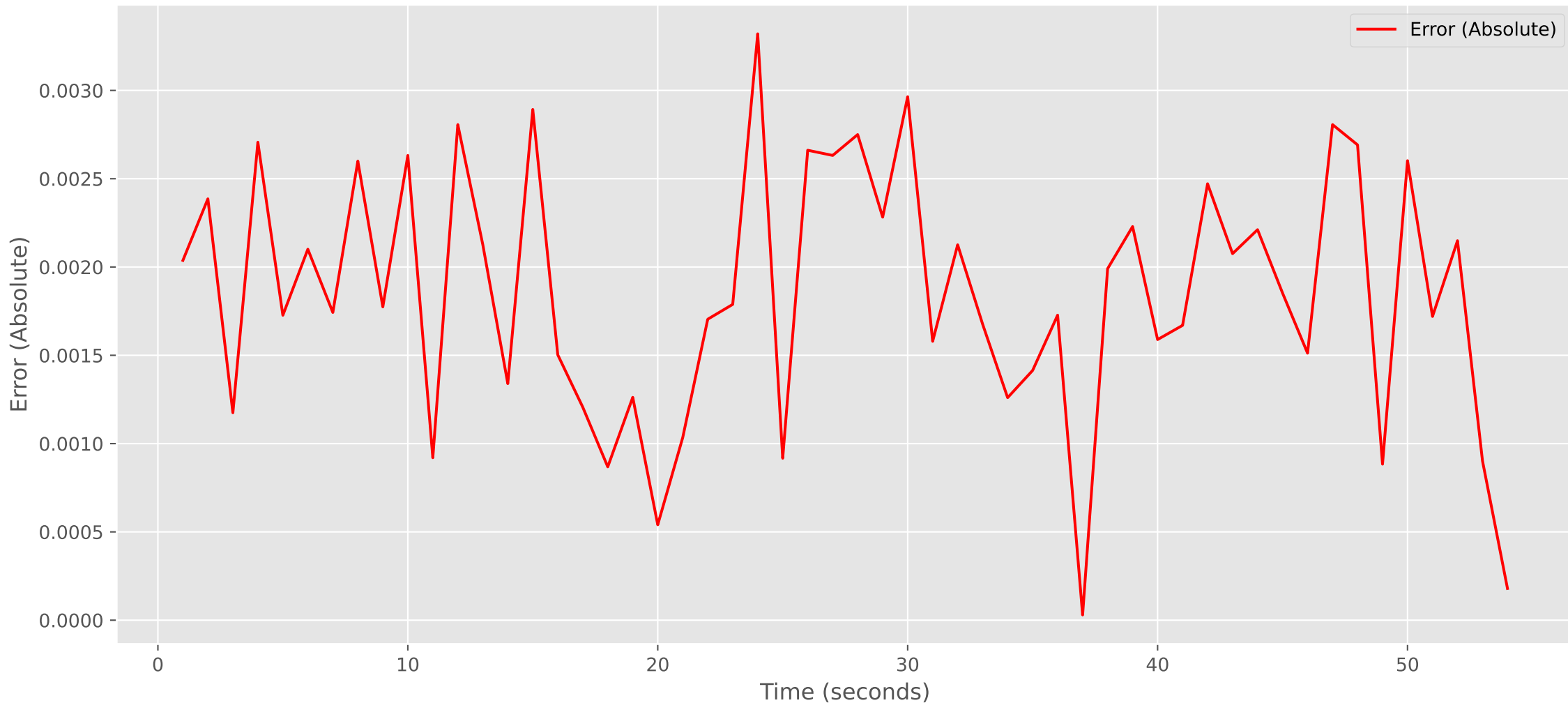
Euler Angles (roll, pitch, yaw) - pitch Error
MAE: 0.0007 | Max Error: 0.0024 | RMSE: 0.0009



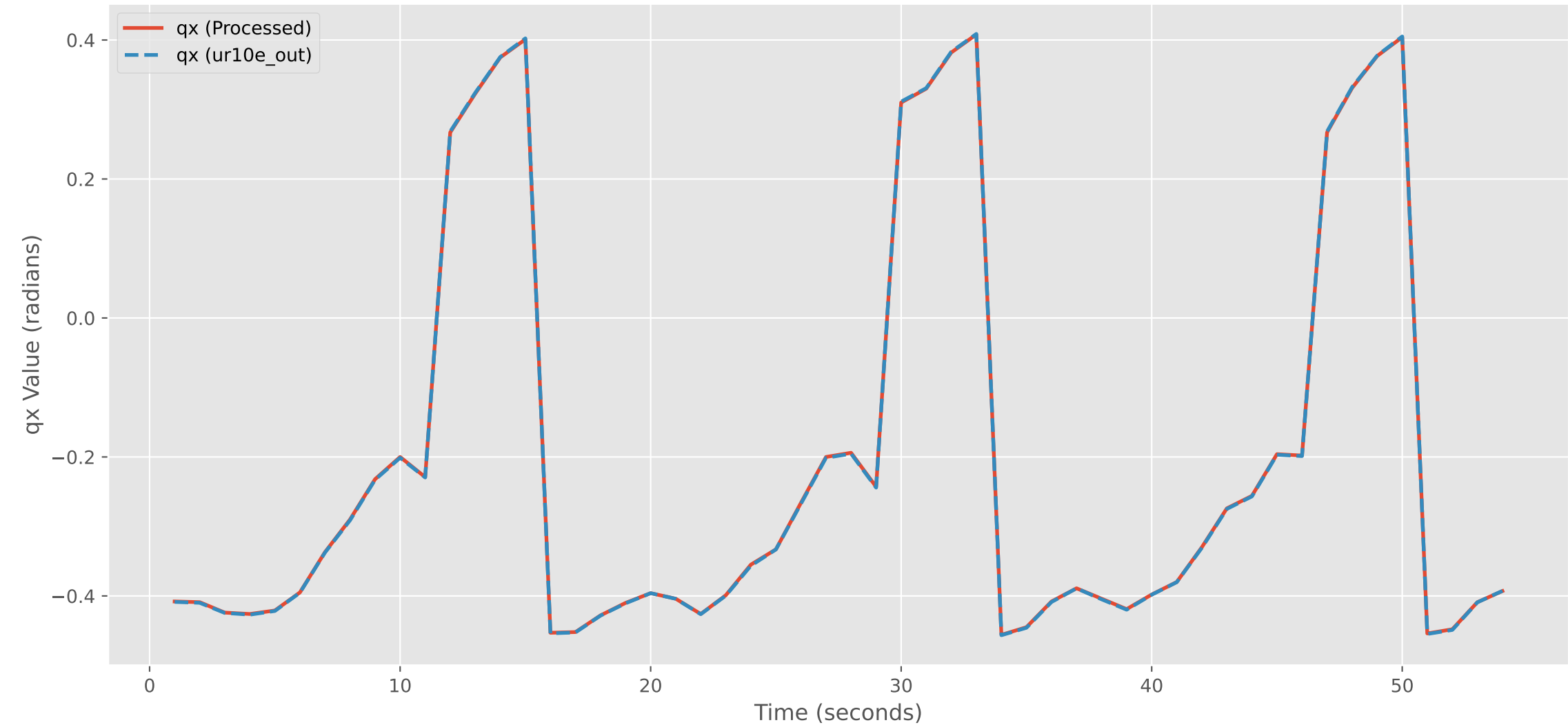
Euler Angles (roll, pitch, yaw) - yaw Comparison



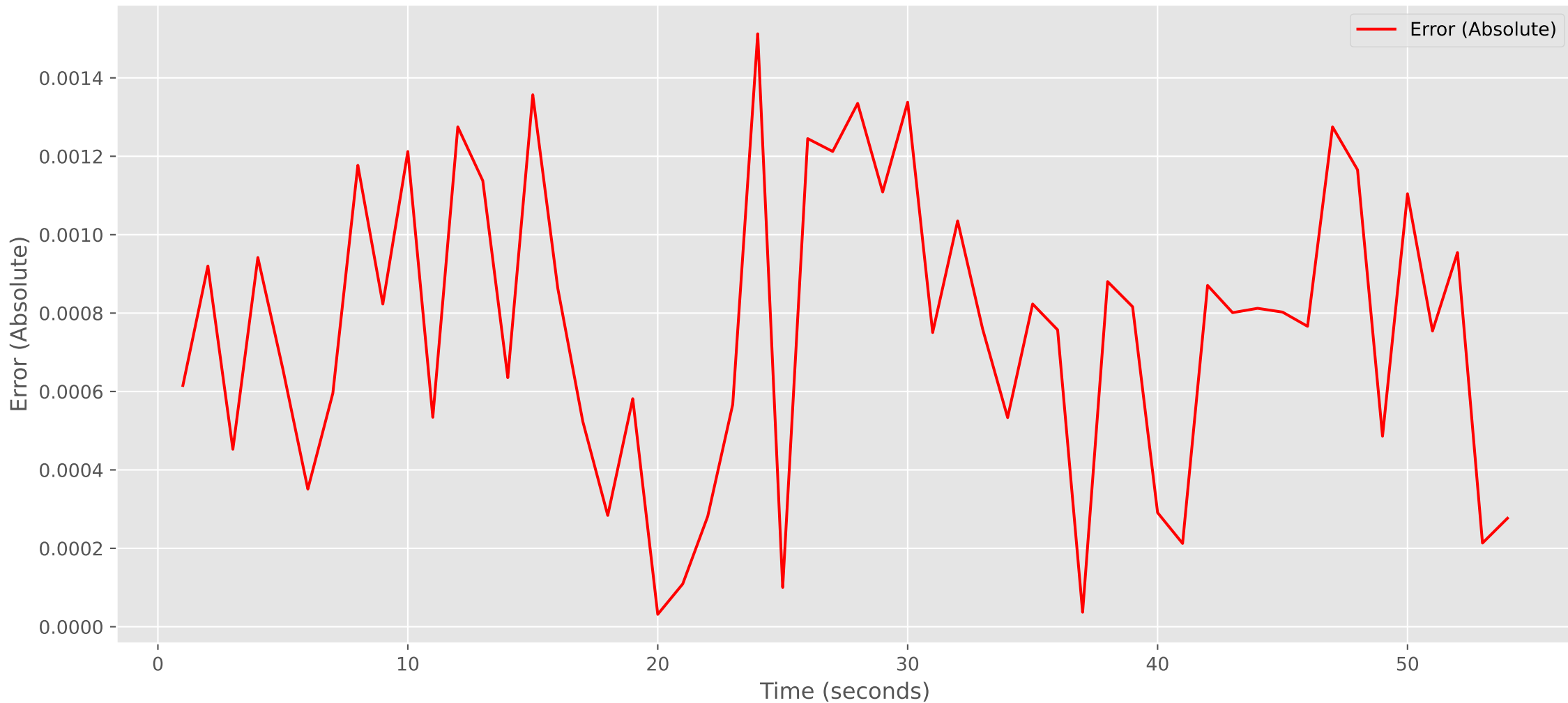
Euler Angles (roll, pitch, yaw) - yaw Error
MAE: 0.0018 | Max Error: 0.0033 | RMSE: 0.0020



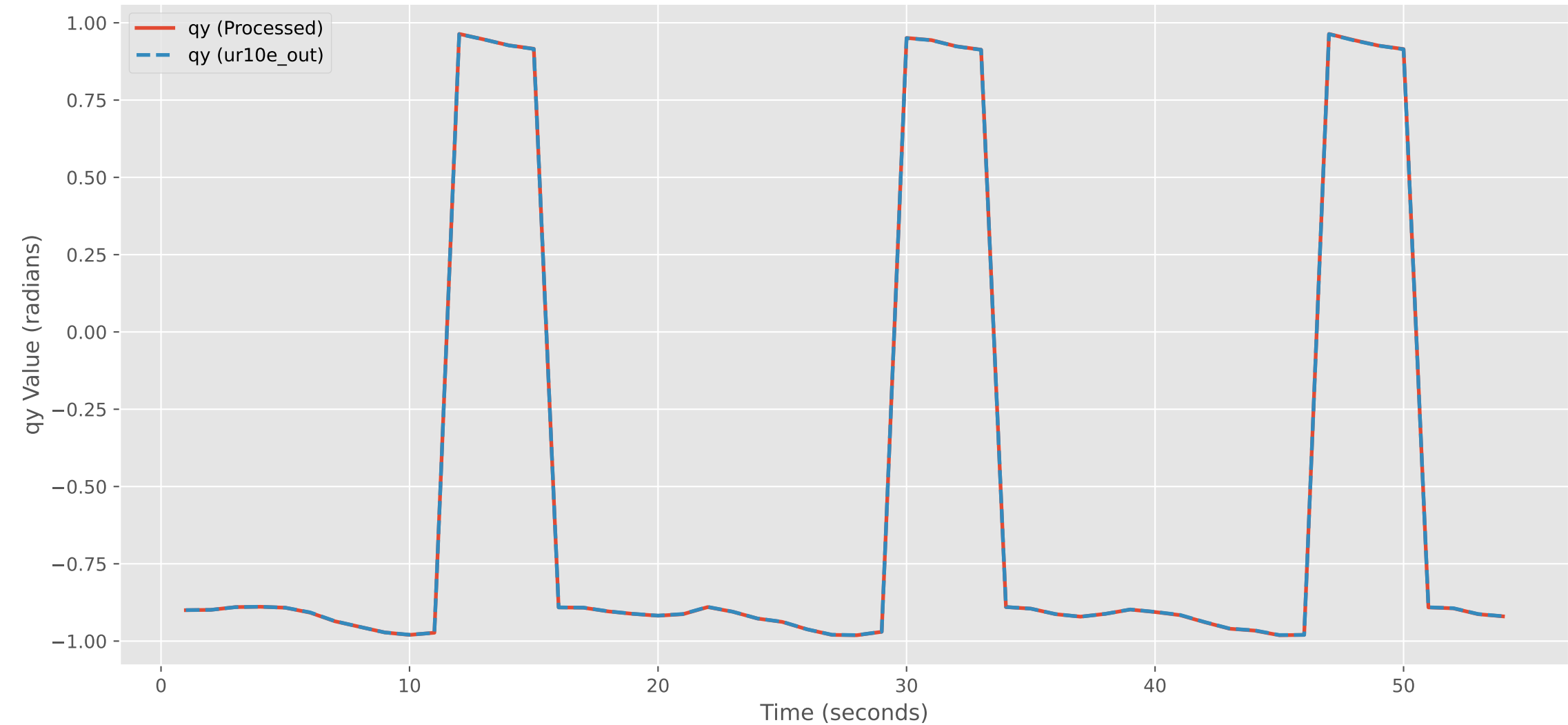
Quaternions (qx, qy, qz, qw) - qx Comparison



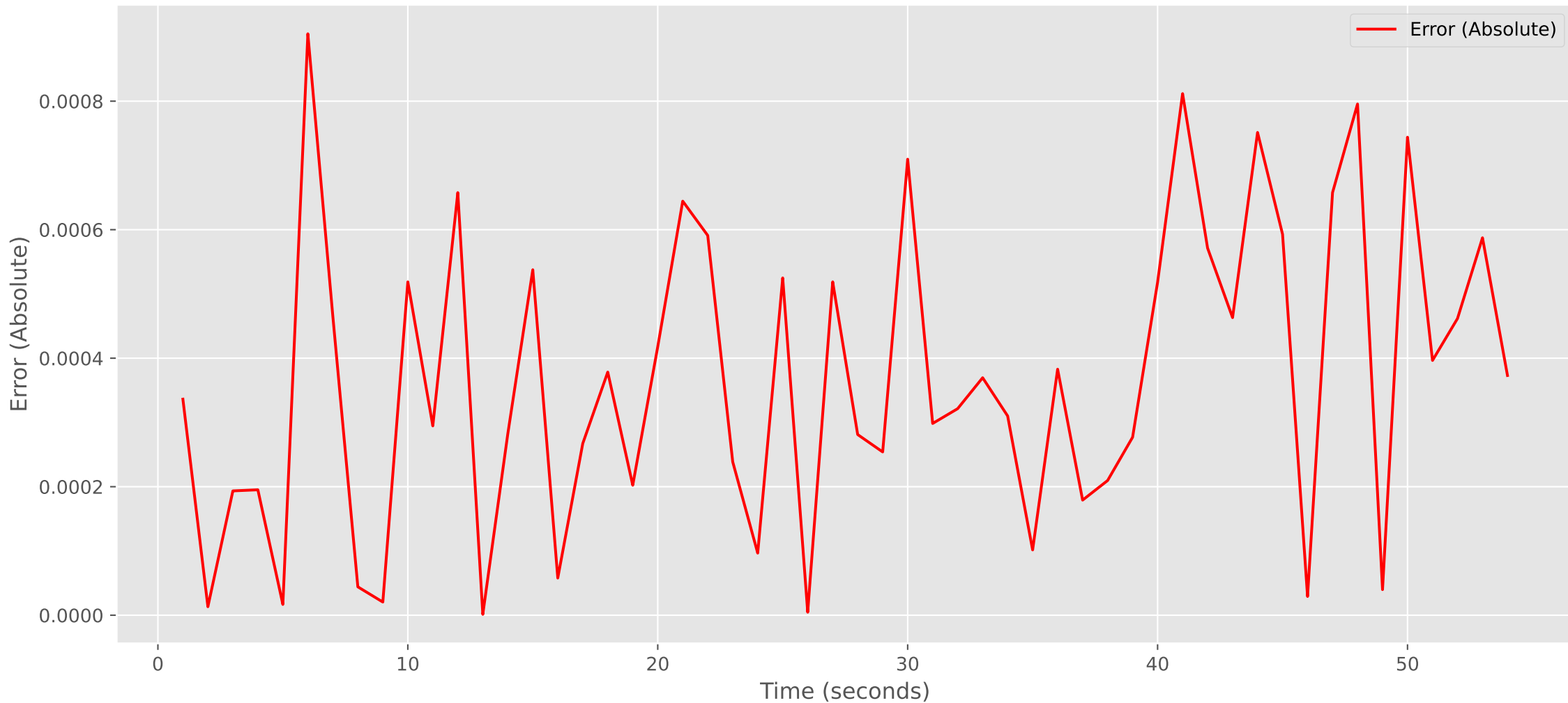
Quaternions (qx, qy, qz, qw) - qx Error
MAE: 0.0008 | Max Error: 0.0015 | RMSE: 0.0008



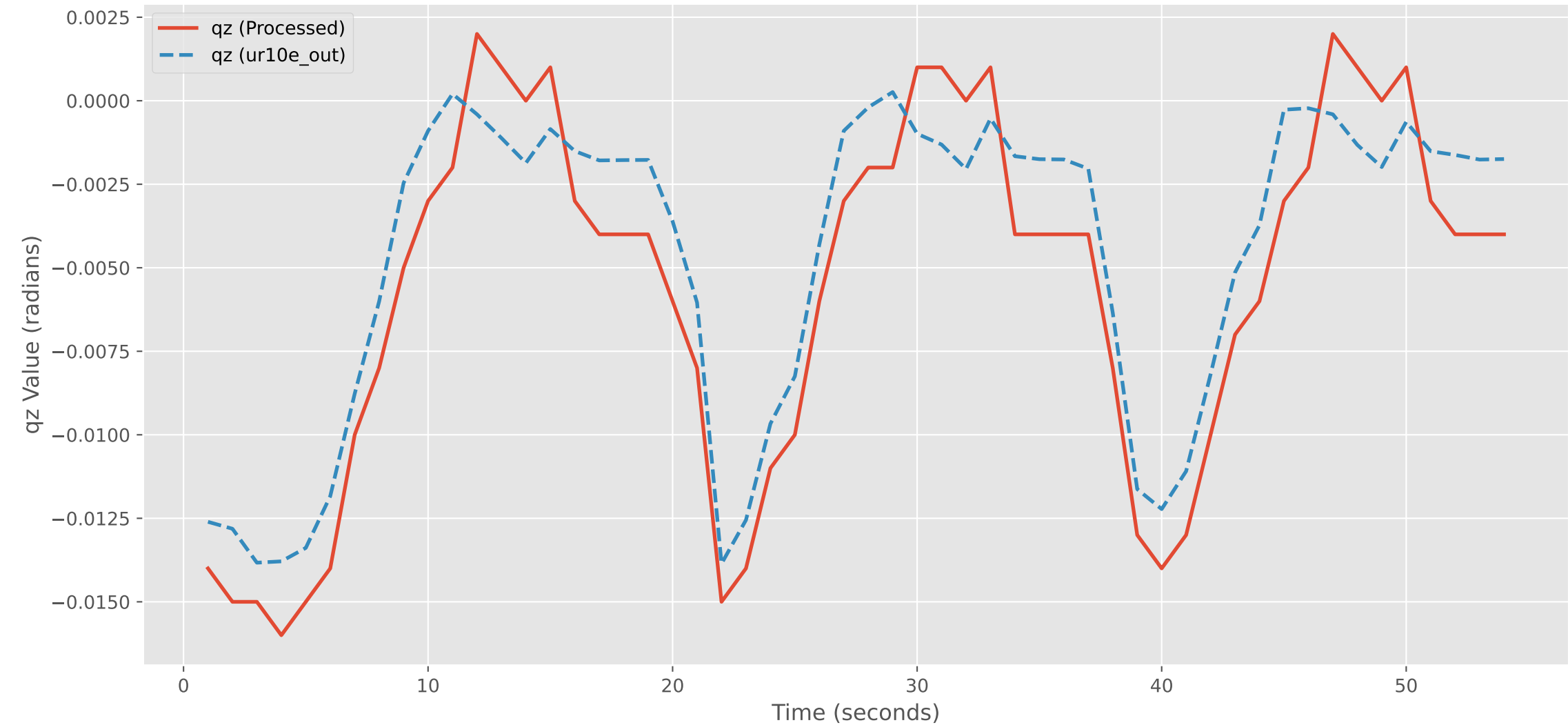
Quaternions (qx, qy, qz, qw) - qy Comparison



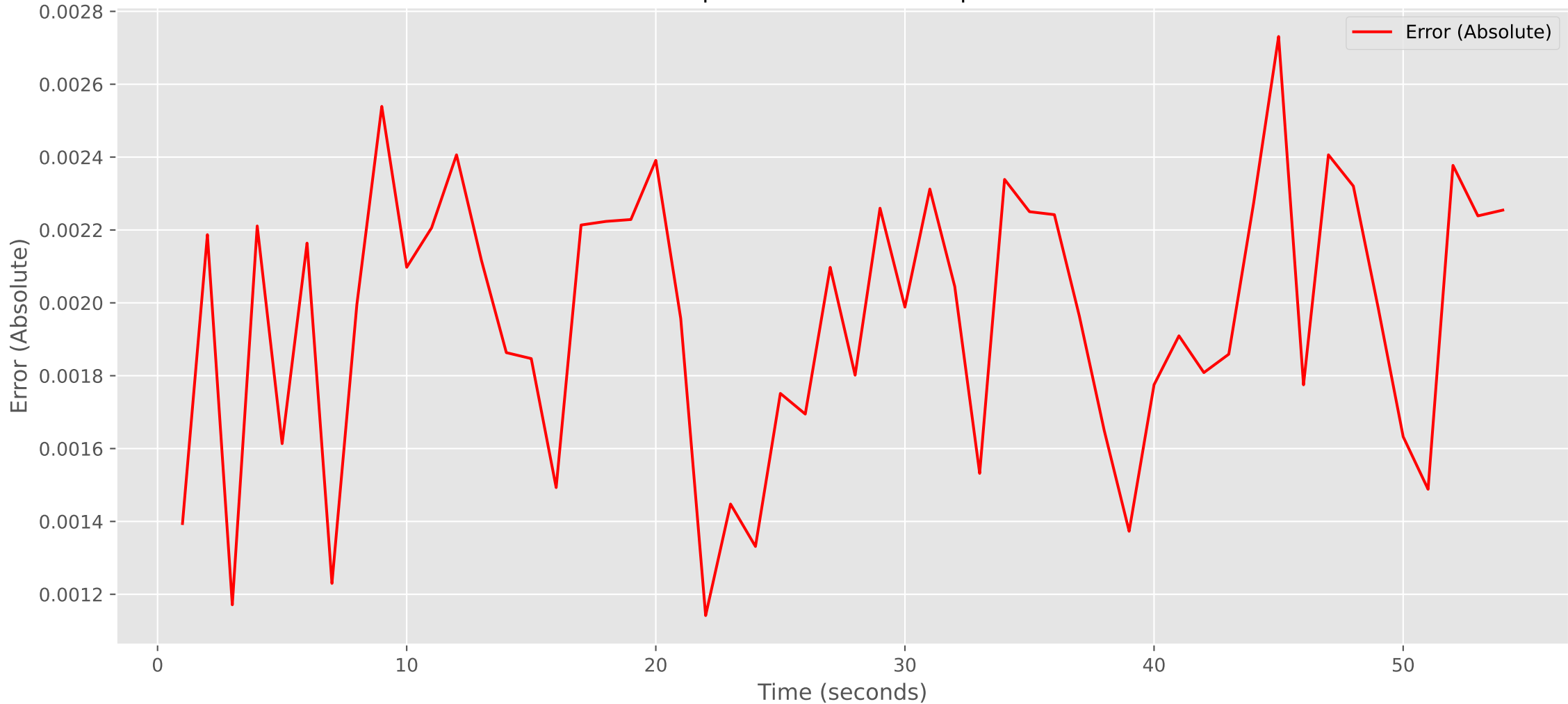
Quaternions (qx, qy, qz, qw) - qy Error
MAE: 0.0004 | Max Error: 0.0009 | RMSE: 0.0004



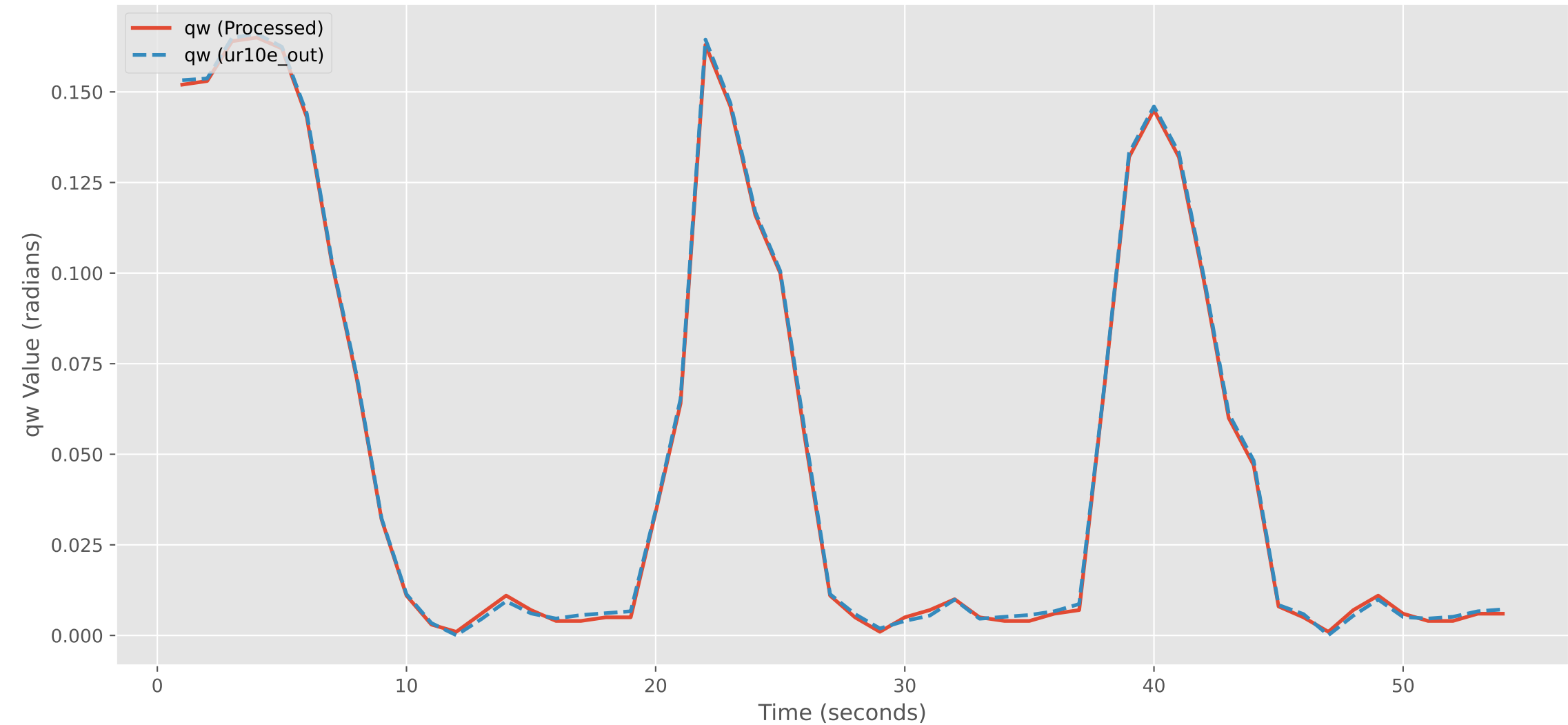
Quaternions (qx, qy, qz, qw) - qz Comparison



Quaternions (qx, qy, qz, qw) - qz Error
MAE: 0.0020 | Max Error: 0.0027 | RMSE: 0.0020



Quaternions (qx, qy, qz, qw) - qw Comparison



Quaternions (qx, qy, qz, qw) - qw Error
MAE: 0.0010 | Max Error: 0.0018 | RMSE: 0.0010

