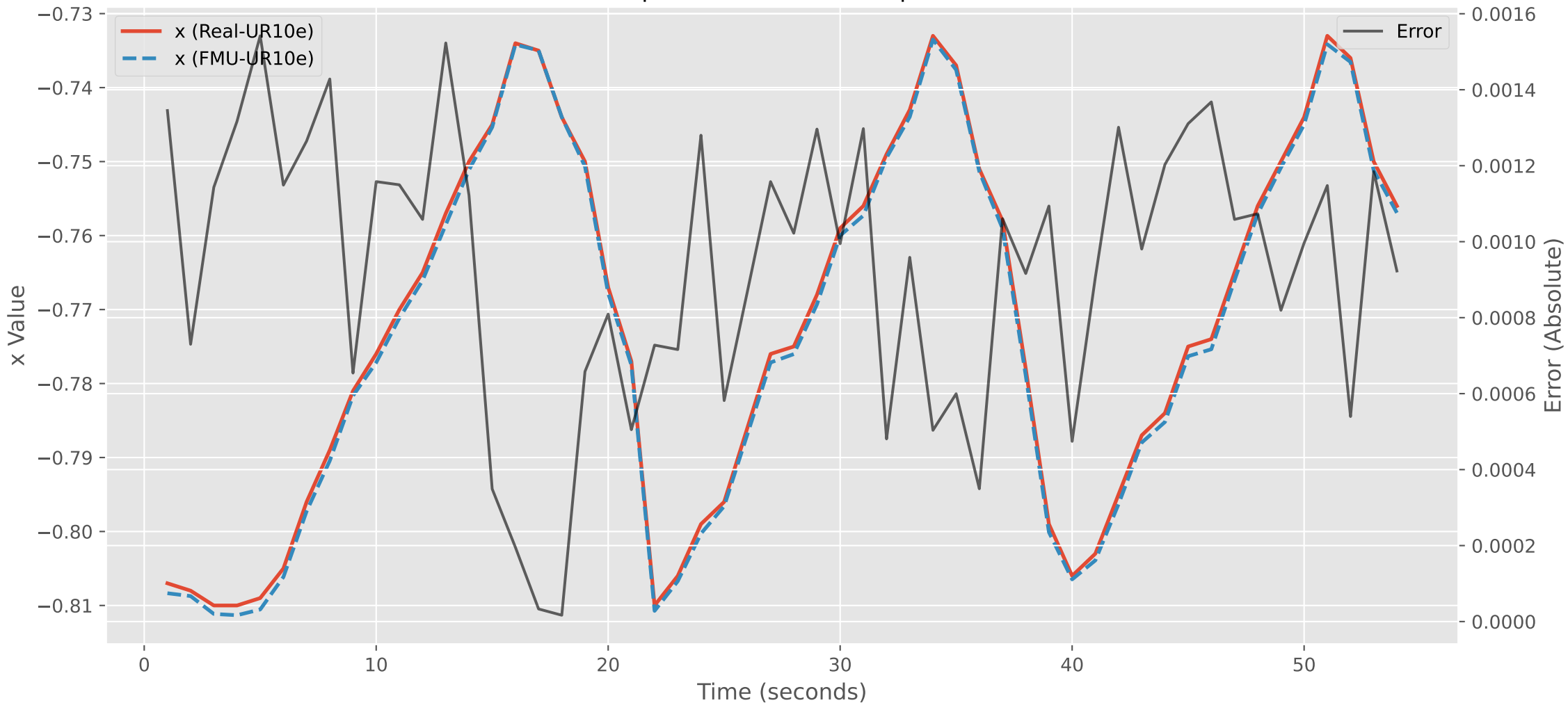
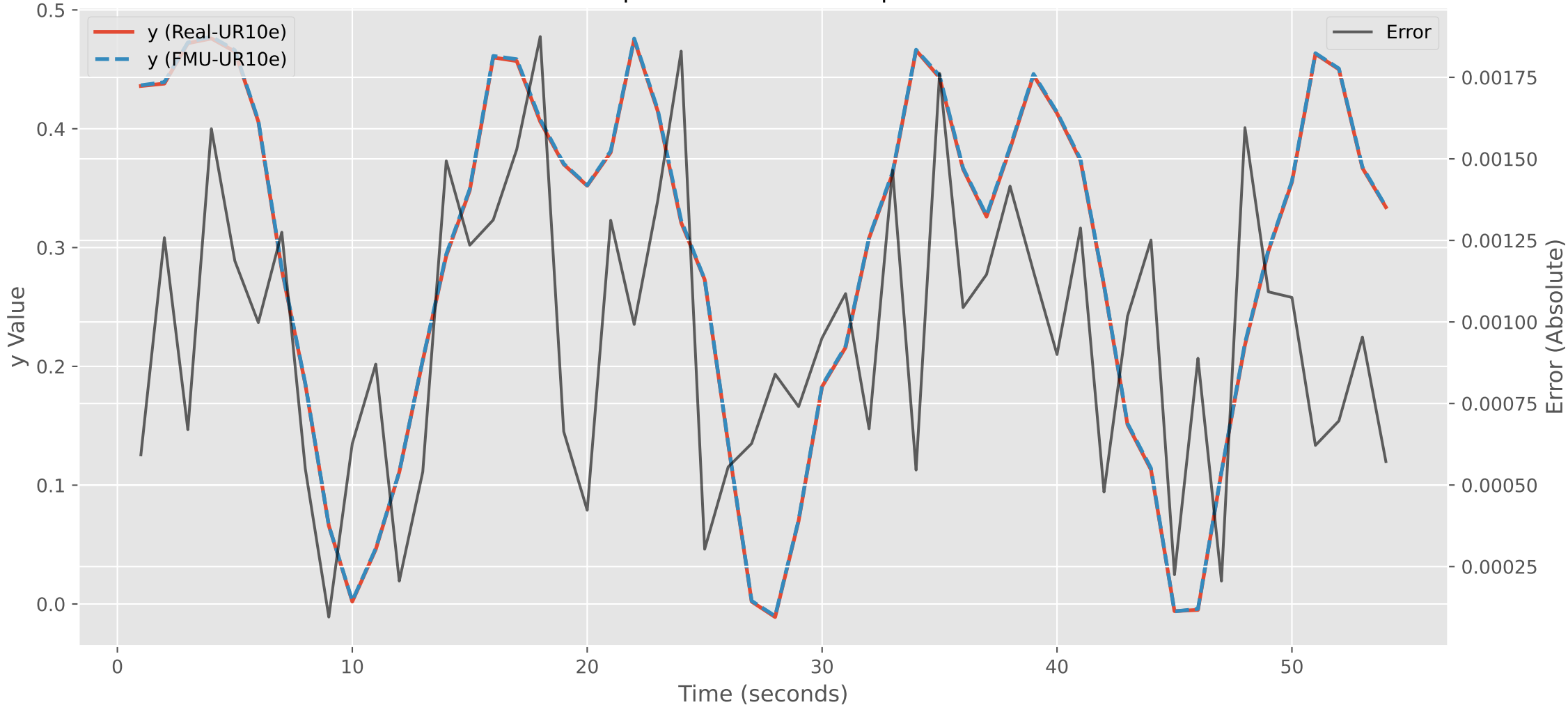


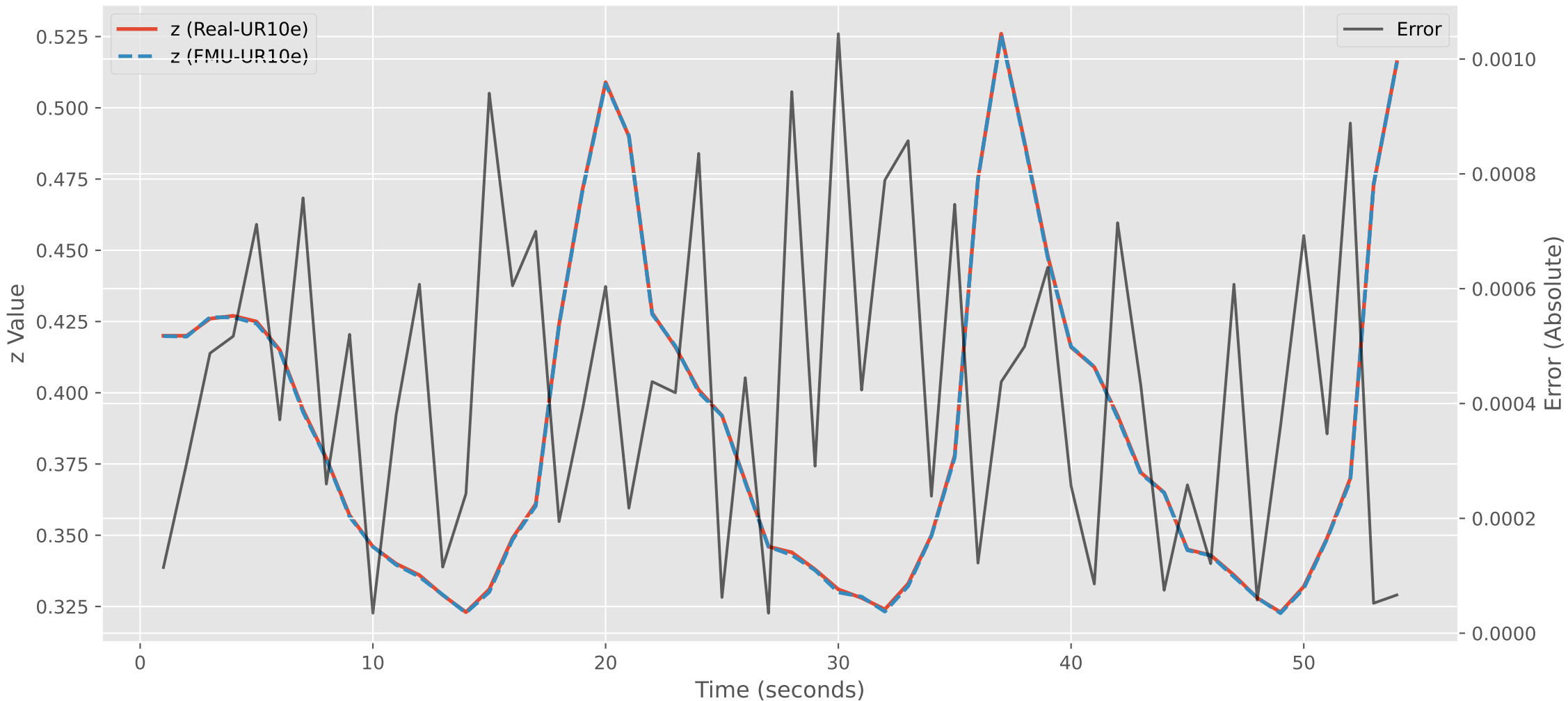
Position (x, y, z) - x Comparison
MAE: 0.0009 | Max Error: 0.0015 | RMSE: 0.0010



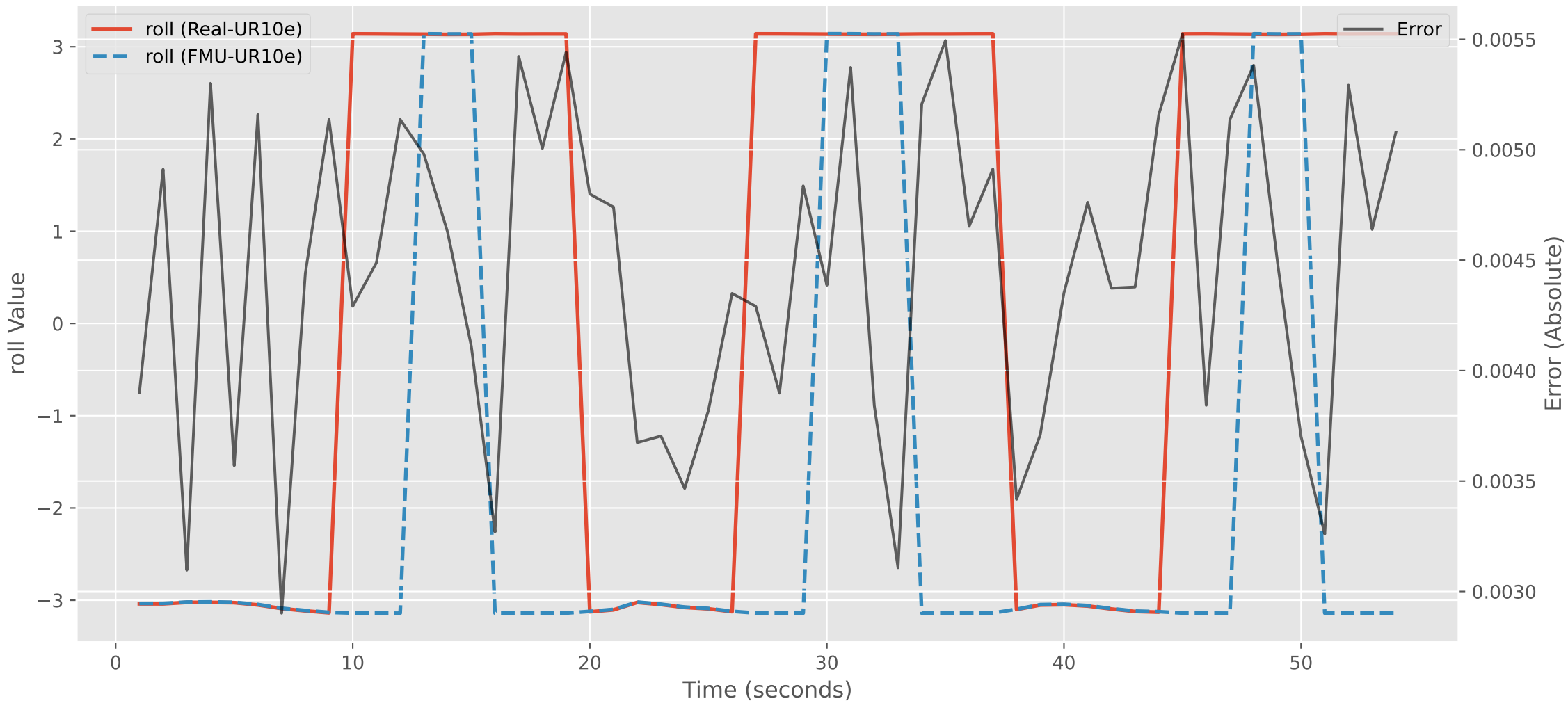
Position (x, y, z) - y Comparison
MAE: 0.0010 | Max Error: 0.0019 | RMSE: 0.0011



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

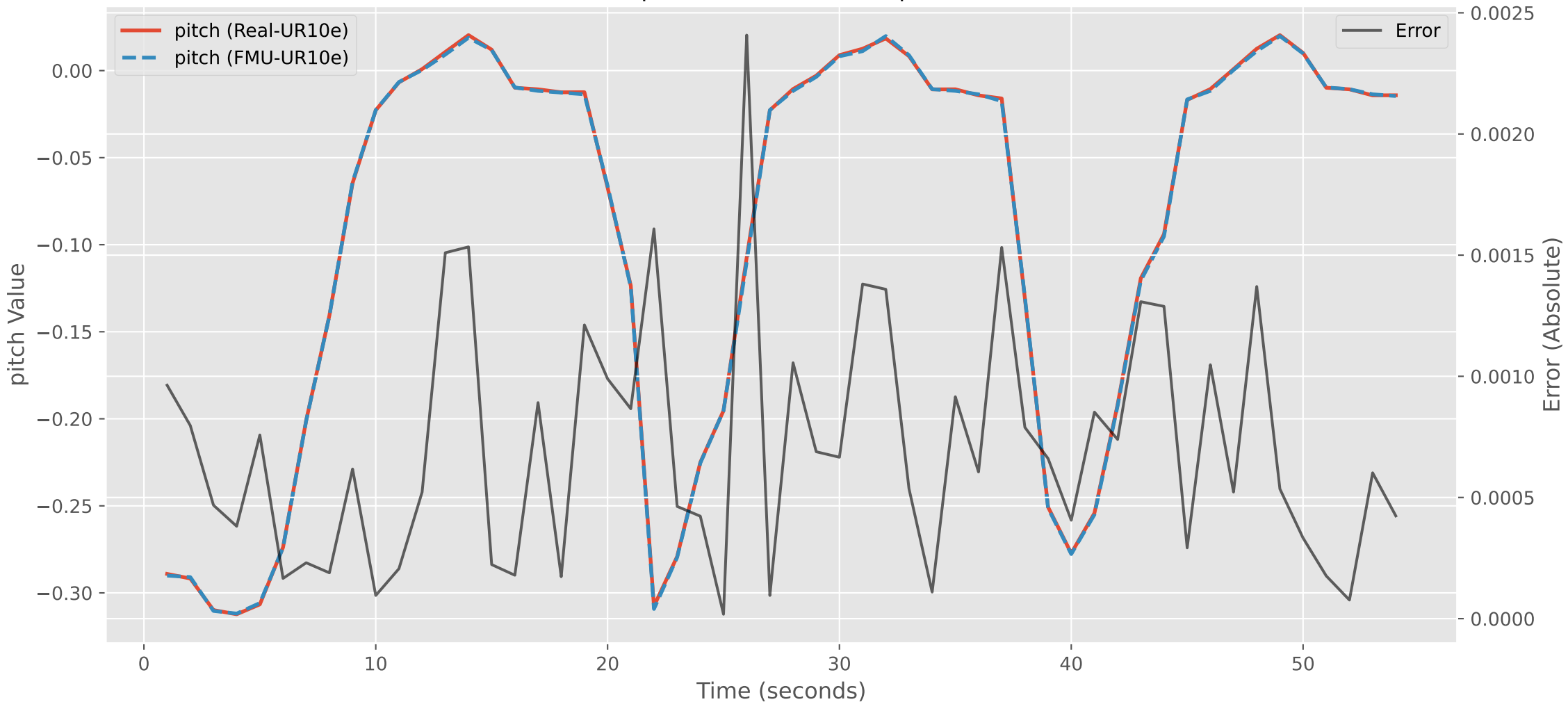


Euler Angles (roll, pitch, yaw) - roll Comparison
MAE: 0.0044 | Max Error: 0.0055 | RMSE: 0.0045

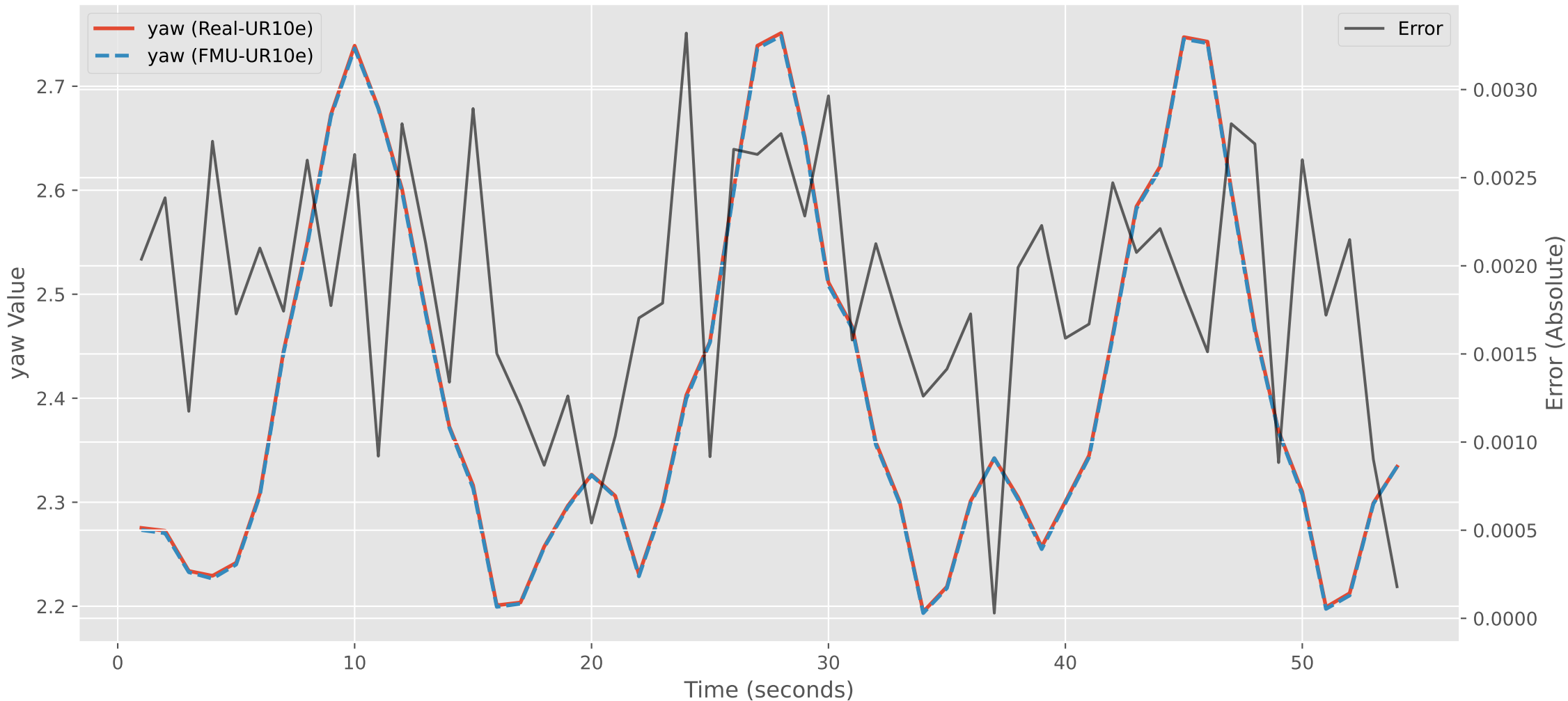


Euler Angles (roll, pitch, yaw) - pitch Comparison

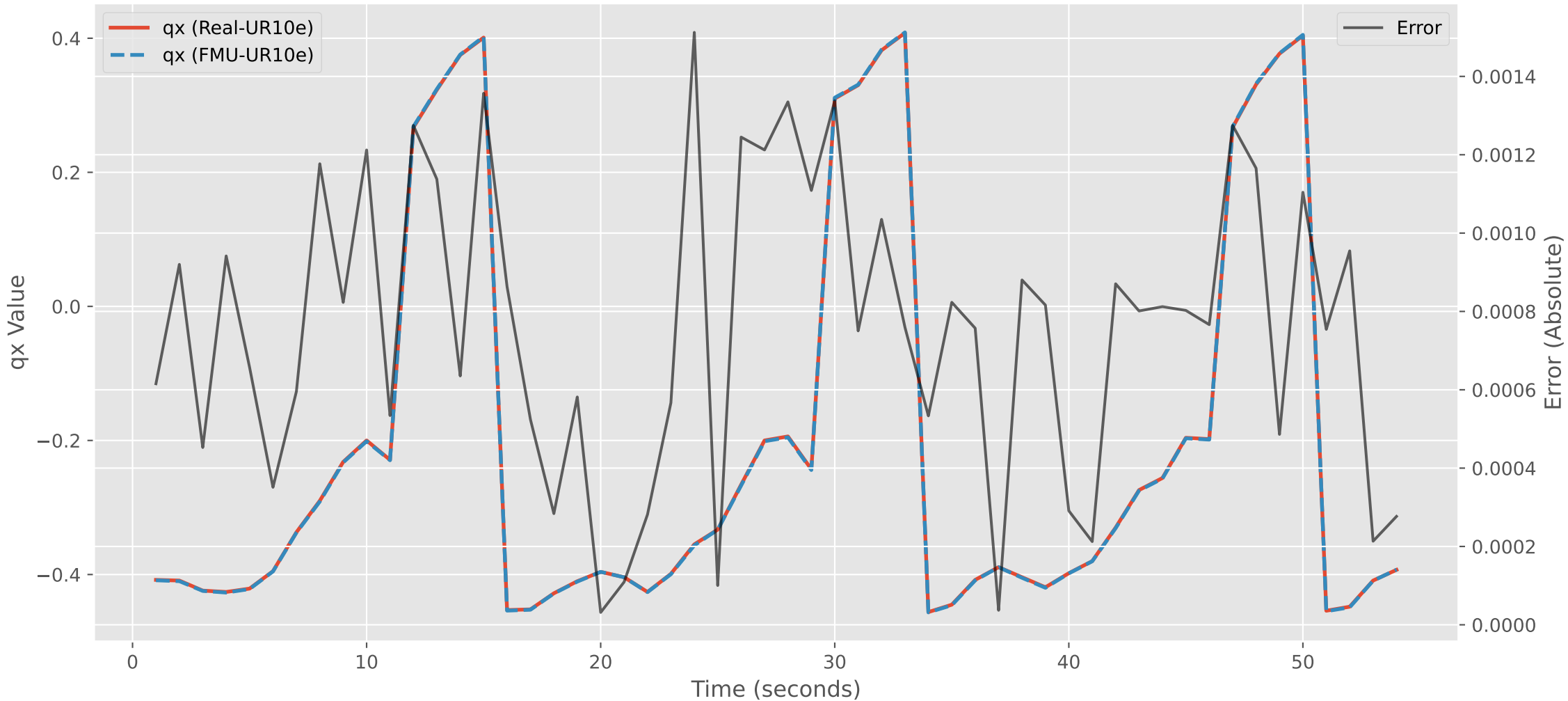
MAE: 0.0007 | Max Error: 0.0024 | RMSE: 0.0009



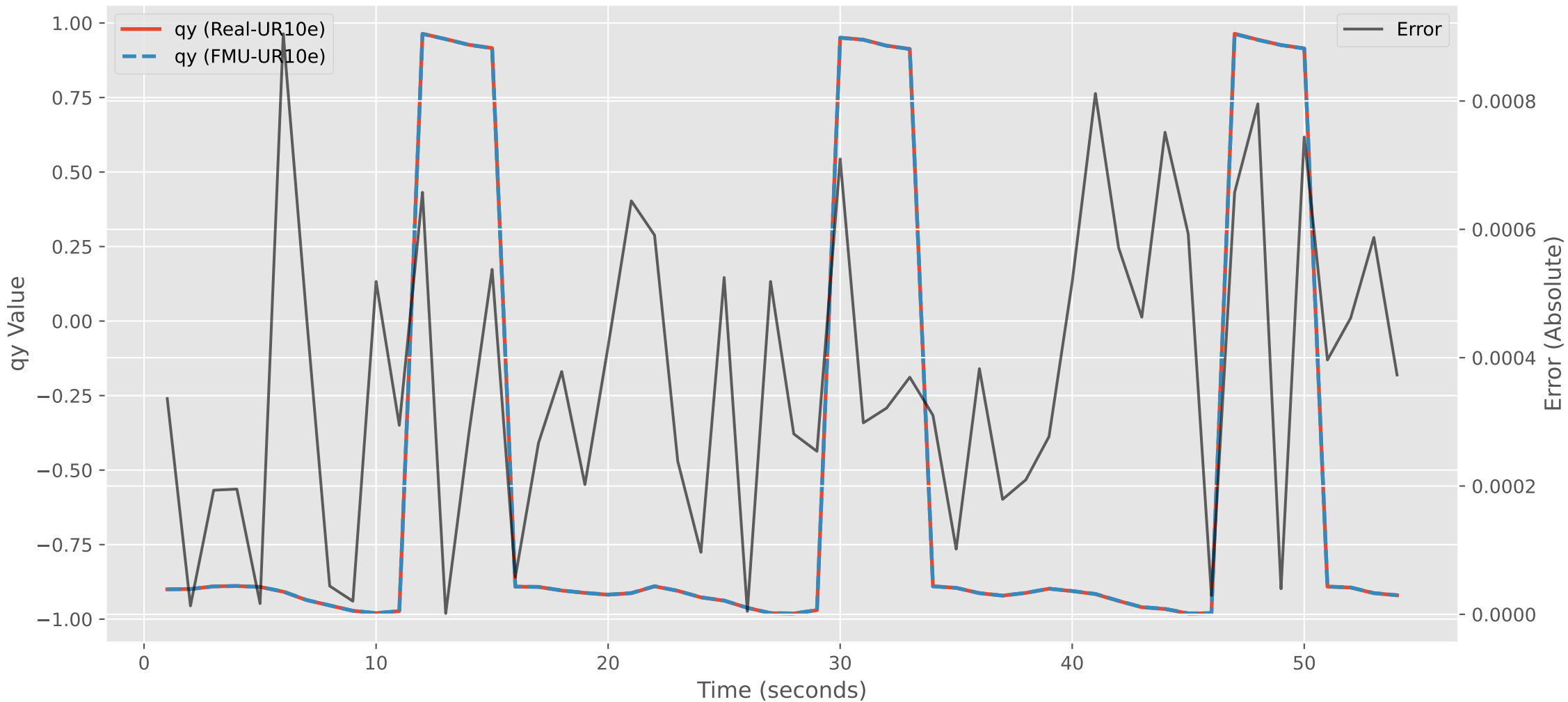
Euler Angles (roll, pitch, yaw) - yaw Comparison
MAE: 0.0018 | Max Error: 0.0033 | RMSE: 0.0020



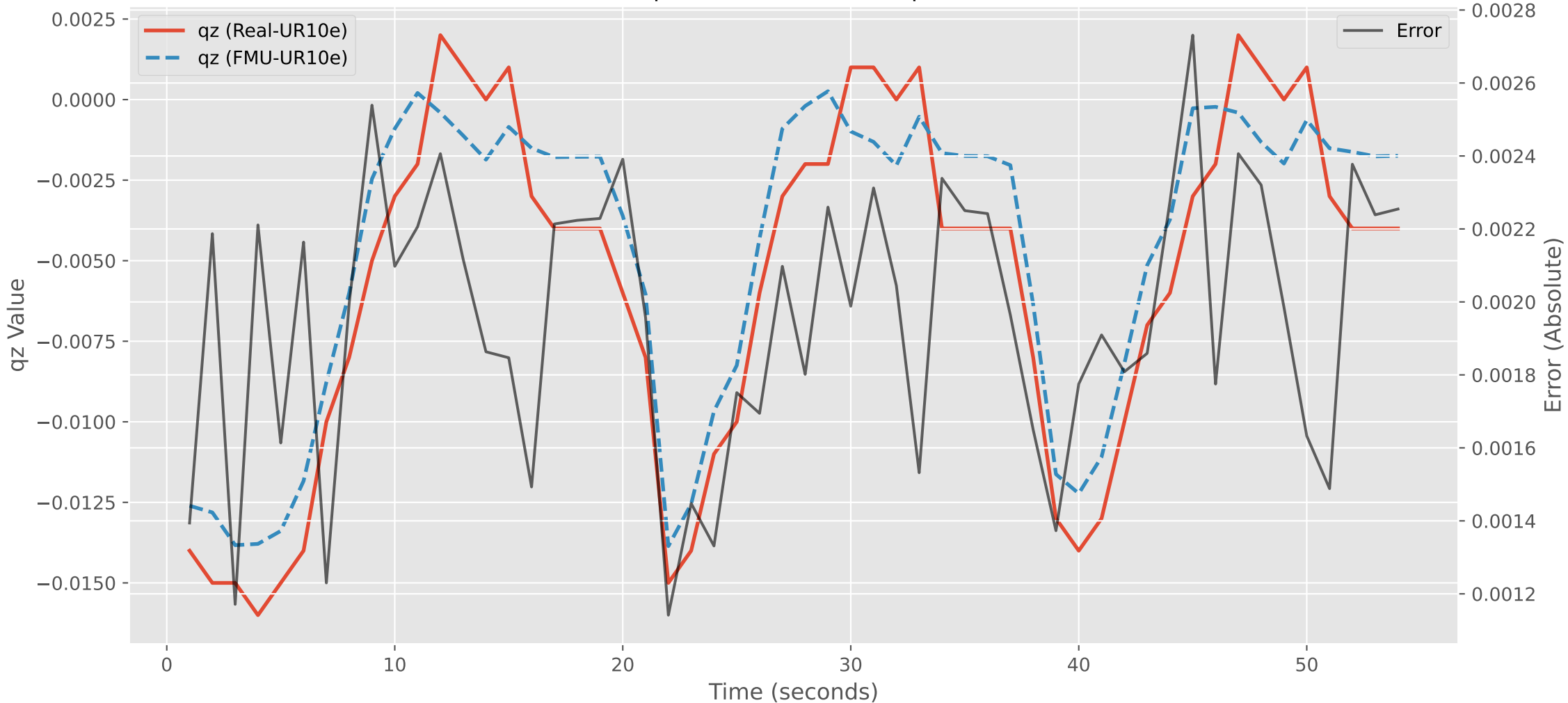
Quaternions (qx, qy, qz, qw) - qx Comparison
MAE: 0.0008 | Max Error: 0.0015 | RMSE: 0.0008



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



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



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

