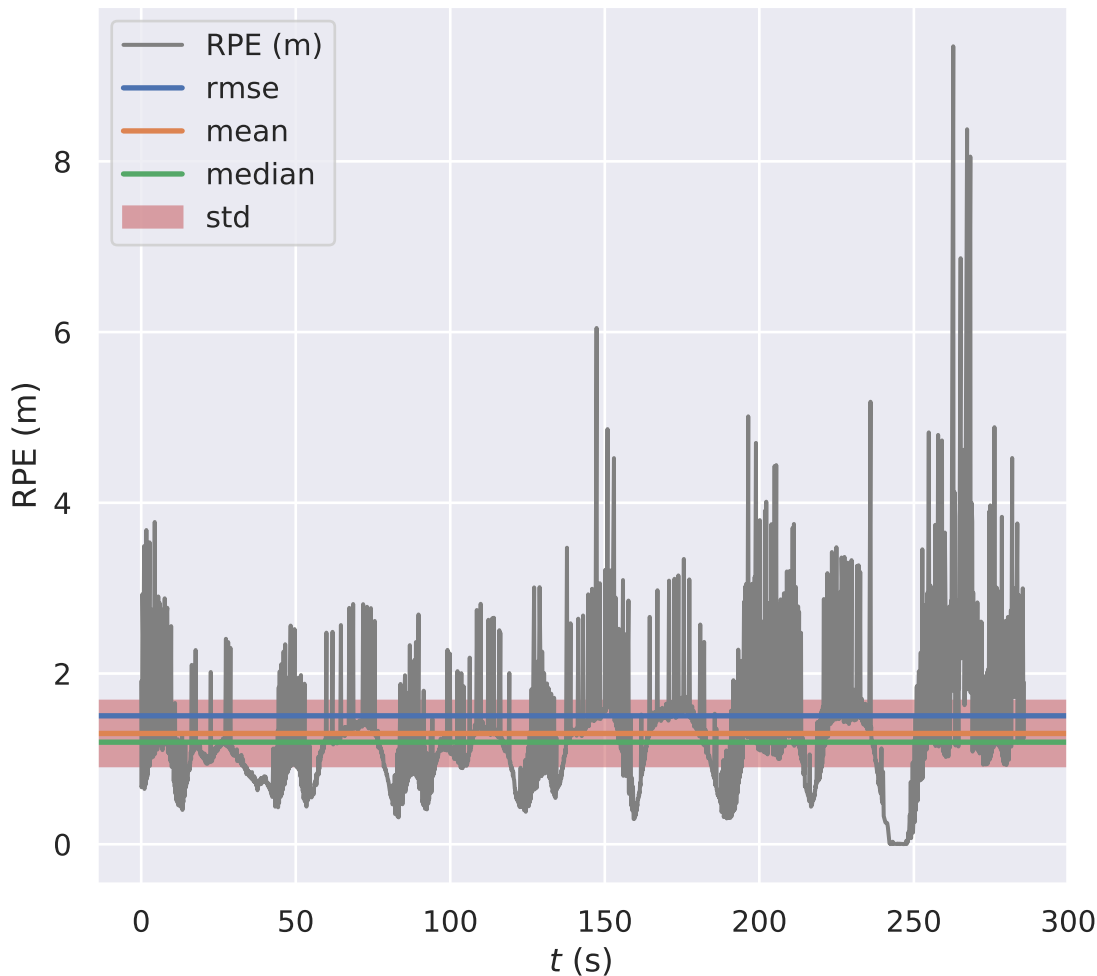


RPE w.r.t. translation part (m)
for delta = m (frames) using consecutive pairs
(with SE(3) Umeyama alignment)



Error mapped onto trajectory

