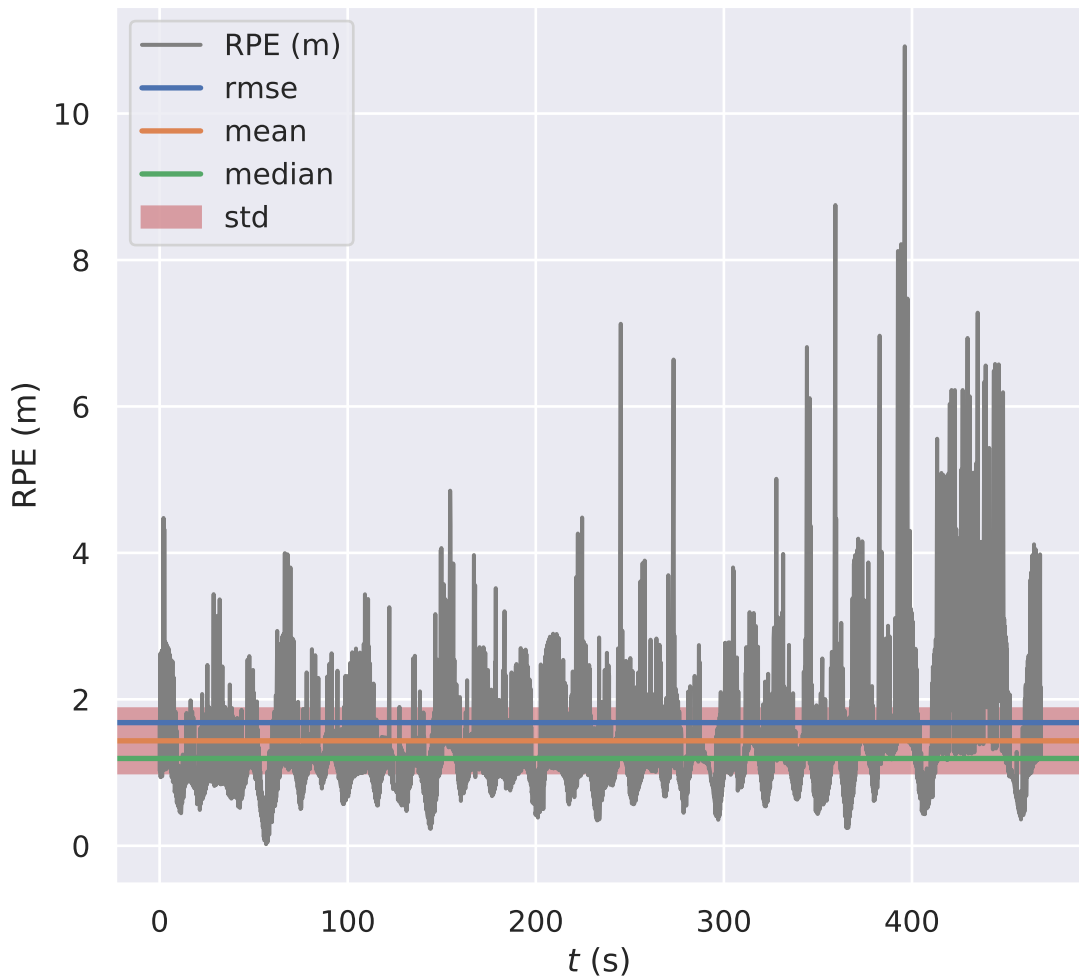


RPE w.r.t. translation part (m)  
for  $\delta = m$  (frames) using consecutive pairs  
(with SE(3) Umeyama alignment)



Error mapped onto trajectory

