Moving (ED frame)
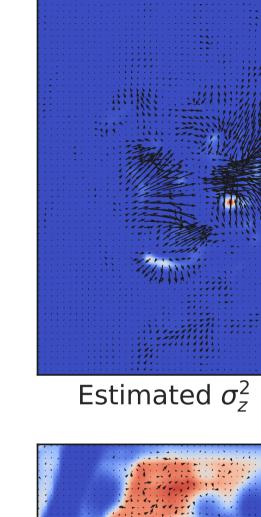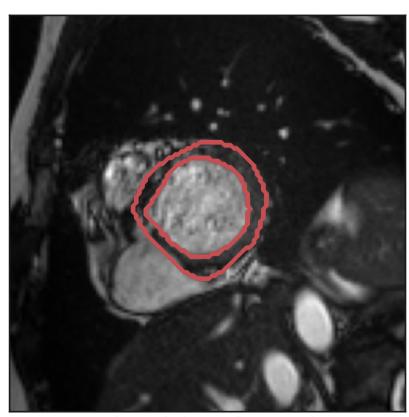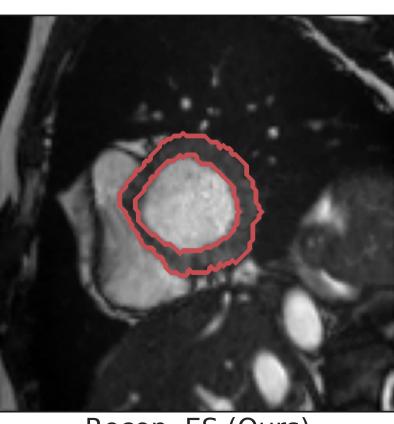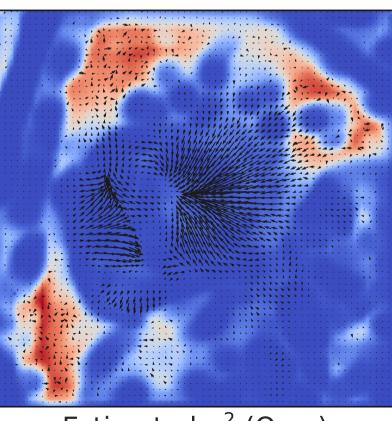
Recon. ES (Vxm-diff)

Estimated σ_z^2 (Vxm-diff)

Fixed (ES frame)

Recon. ES (Ours)

Estimated σ_z^2 (Ours)