from trigonometry import cos

$$\varepsilon\_symm = \sum_{i} cos\left(\theta\right)^{2} \left(\left(p_{i} - q_{i}\right) \cdot n_{i} + \left(\left(p_{i} + q_{i}\right) \times n_{i}\right) \cdot \tilde{a} + n_{i} \cdot \tilde{t}\right)^{2}$$

where

- $\theta \in \mathbb{R}$ angle of rotation
- $p_{i} \in \mathbb{R}^{3}$
- $q_{i} \in \mathbb{R}^{3}$
- $n_{i} \in \mathbb{R}^{3}$
- $\tilde{a} \in \mathbb{R}^{3}$
- $\tilde{t} \in \mathbb{R}^{3}$