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

$$\begin{aligned}
\theta &\in \mathbb{R} \text{ angle of rotation} \\
p_{i} &\in \mathbb{R}^{3} \\
q_{i} &\in \mathbb{R}^{3} \\
n_{i} &\in \mathbb{R}^{3} \\
\tilde{a} &\in \mathbb{R}^{3} \\
\tilde{t} &\in \mathbb{R}^{3}
\end{aligned}$$