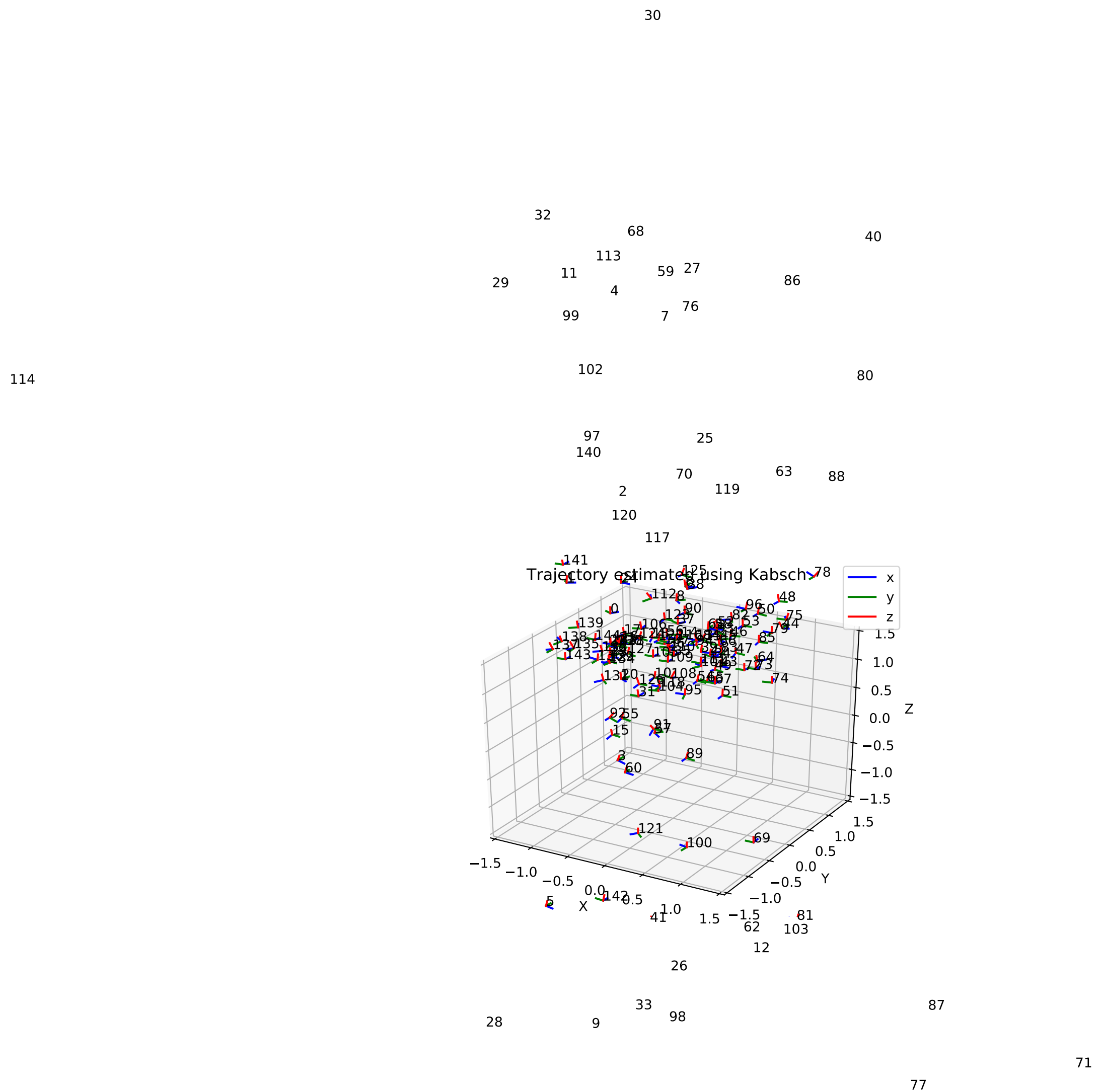
Trajectory estimated using Kabsch
x
y
z
X
Y
Z