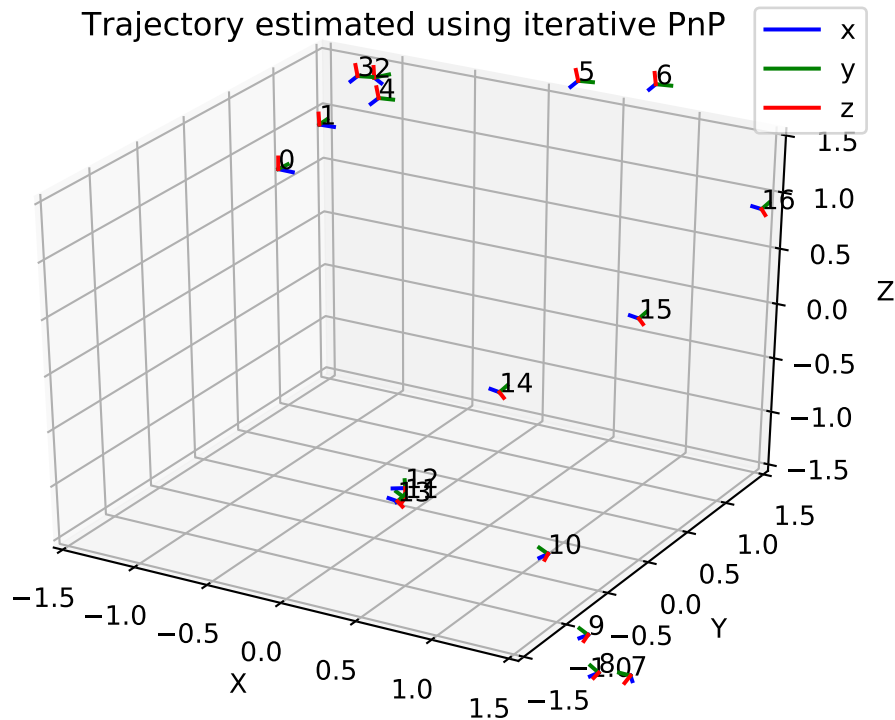


Trajectory estimated using iterative PnP



170

20

22123