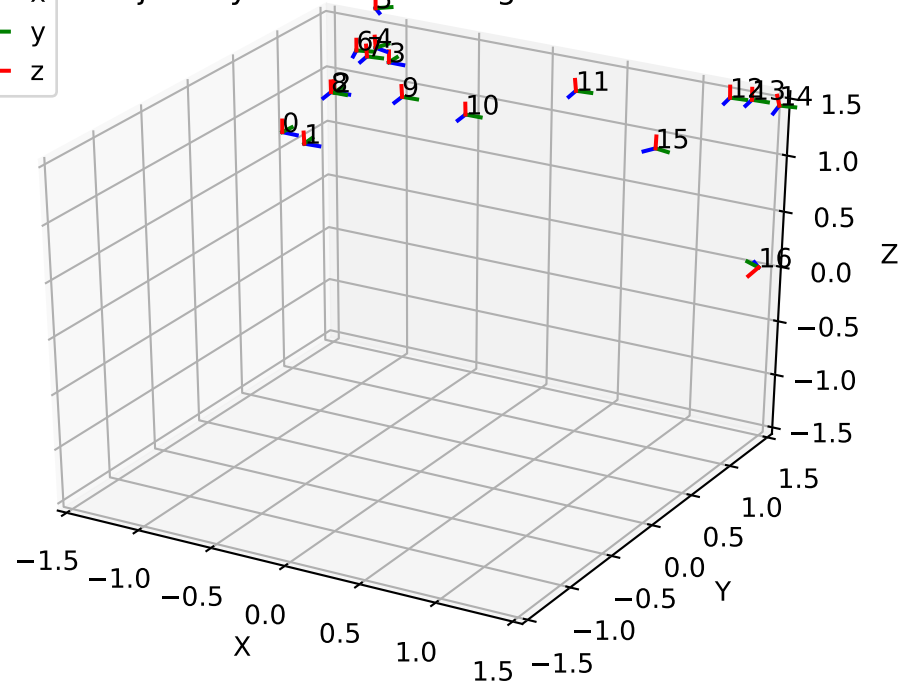


Trajectory estimated using iterative PnP



17 18 20

30 31
28 29 32
27 26 25 24 23

32

33 34

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40 38 39 41

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44 45

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47 48

49 50 51