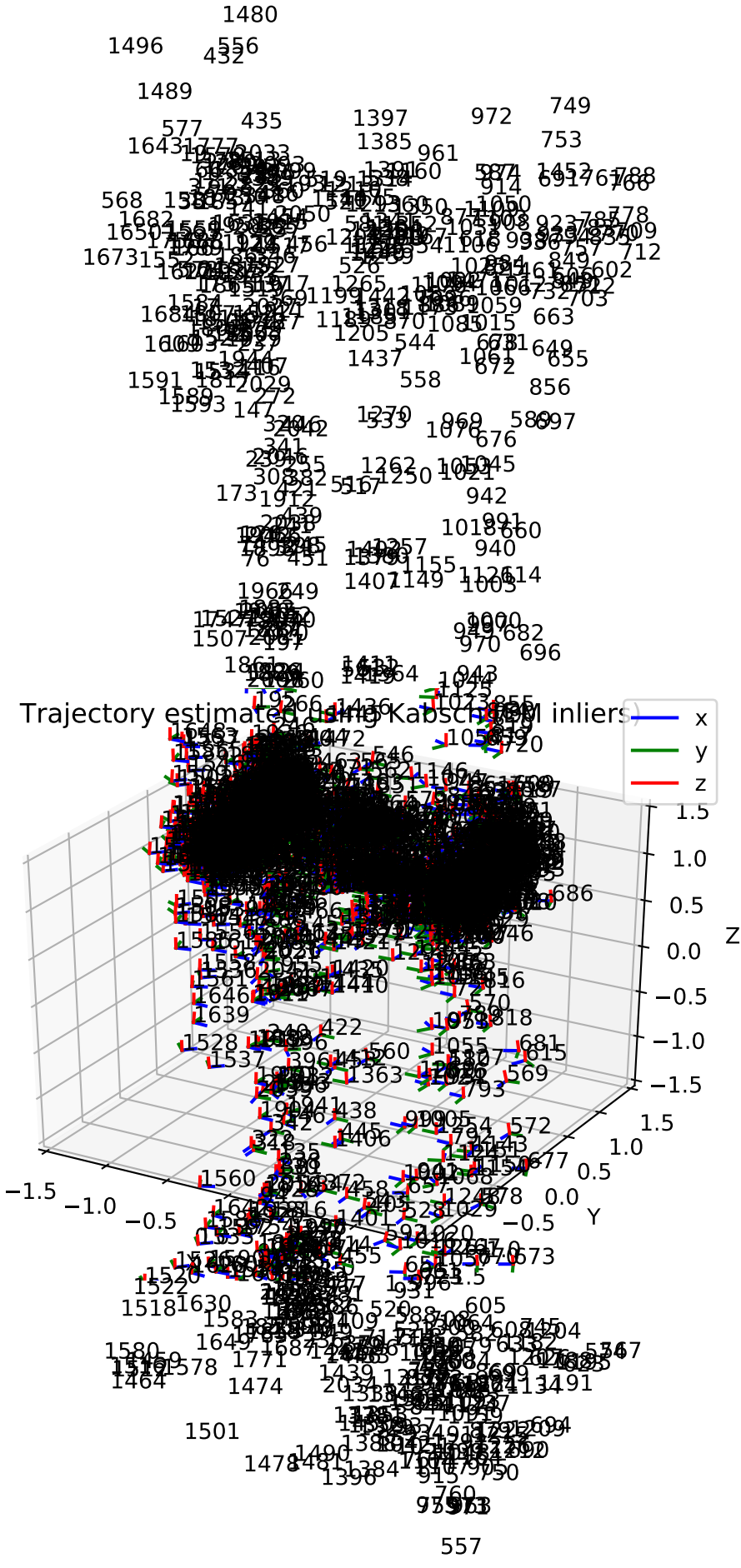
Trajectory estimated using Kabsch RANSAC inliers
x
y
z
Z
Y