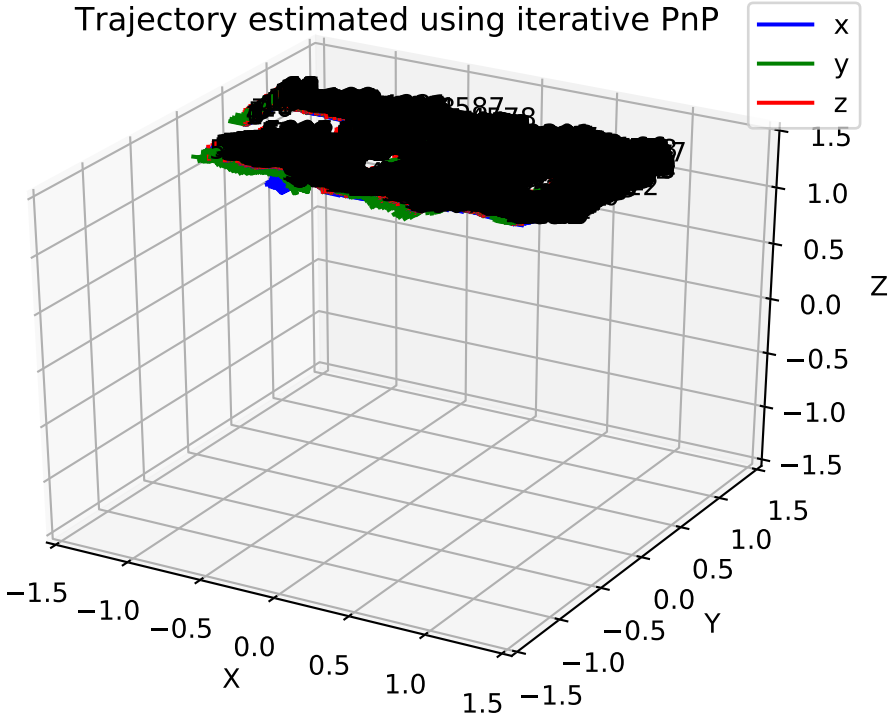
Trajectory estimated using iterative PnP
x
y
z
X
Y
Z
−1.5
−1.0
−0.5
0.0
0.5
1.0
1.5