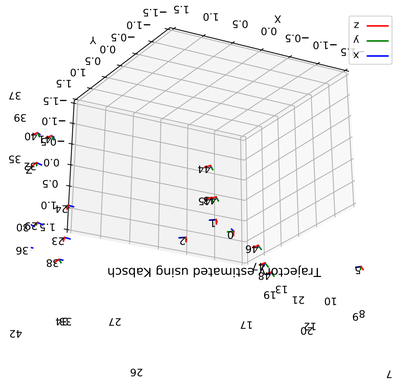
Trajectory estimated using Kabsch
x
y
z