Trajectory estimated using Essential Matrix У ď Z 1.5 1.0 0.5 Z 0.0 -0.5 -1.0 -1 1.5 1.0 0.5 0.0 -0.5 Y -1.0 1.5 -1 -1.5 -1.0 _{-0.5}

0.0 X

0.5

1.0