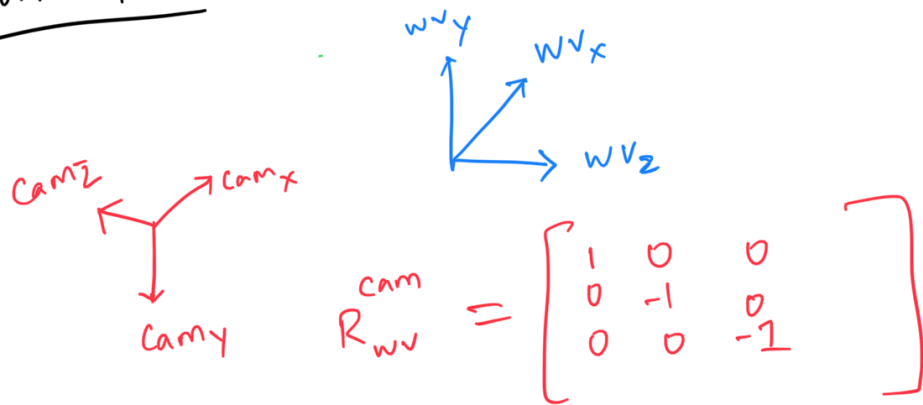


Rotation Offset



$$R_{wv}^{cam} = R \quad \text{markers } R_{wv}^{init}$$

$$R = R_{wv}^{cam} @ \quad \text{wv } R_{wv}^{init} \text{ markers}$$

Yaw \approx rotation along cam_y axis
or: dot product cam_z axis with reference



$\theta \approx$ yaw angle

$$\theta = \arccos(\text{cam}_z \cdot \text{cam}_z)$$