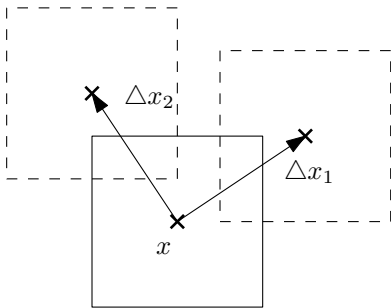


Potential positions of the same point in the next frame



Neighbourhood of the point in previous frame