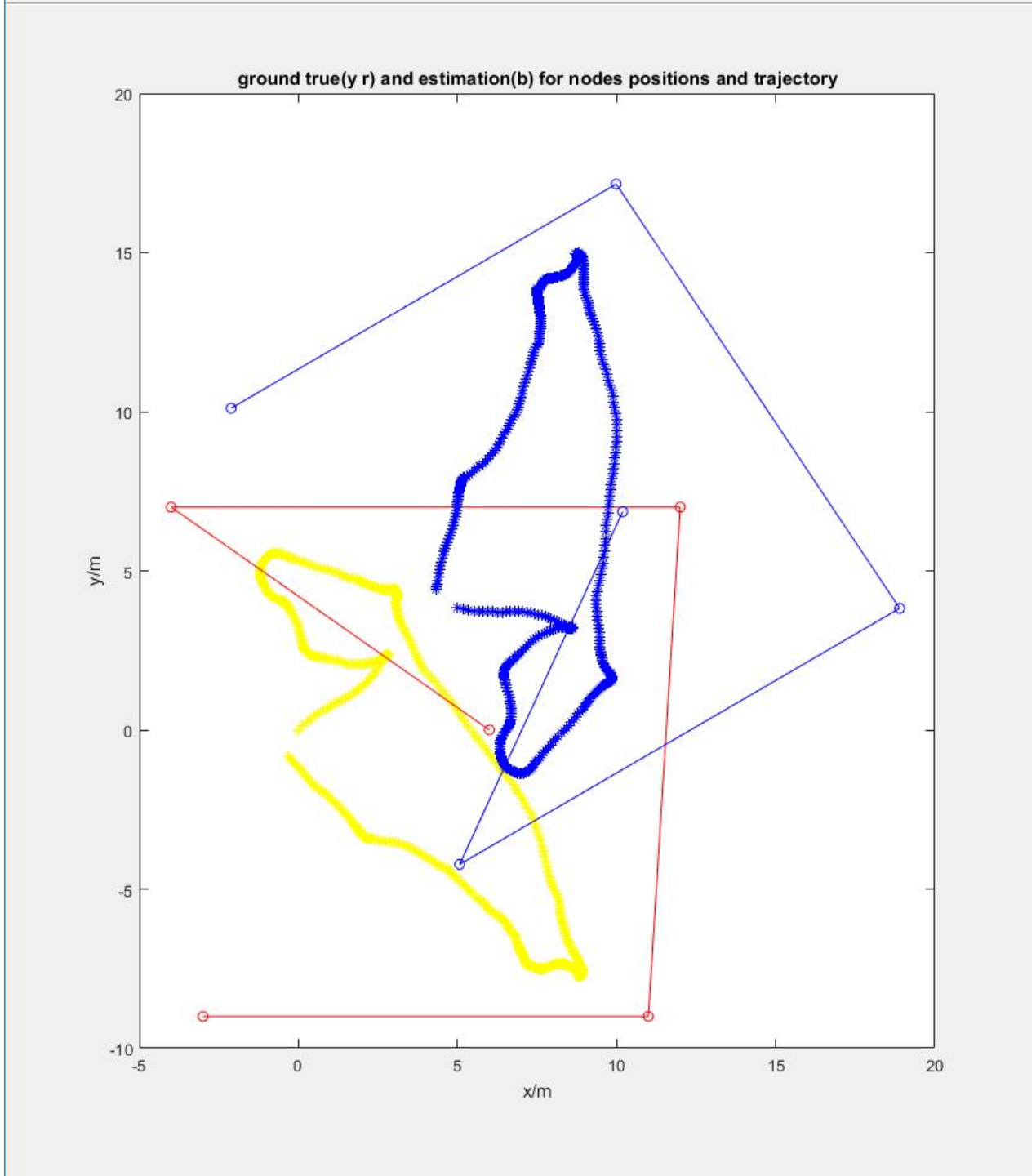
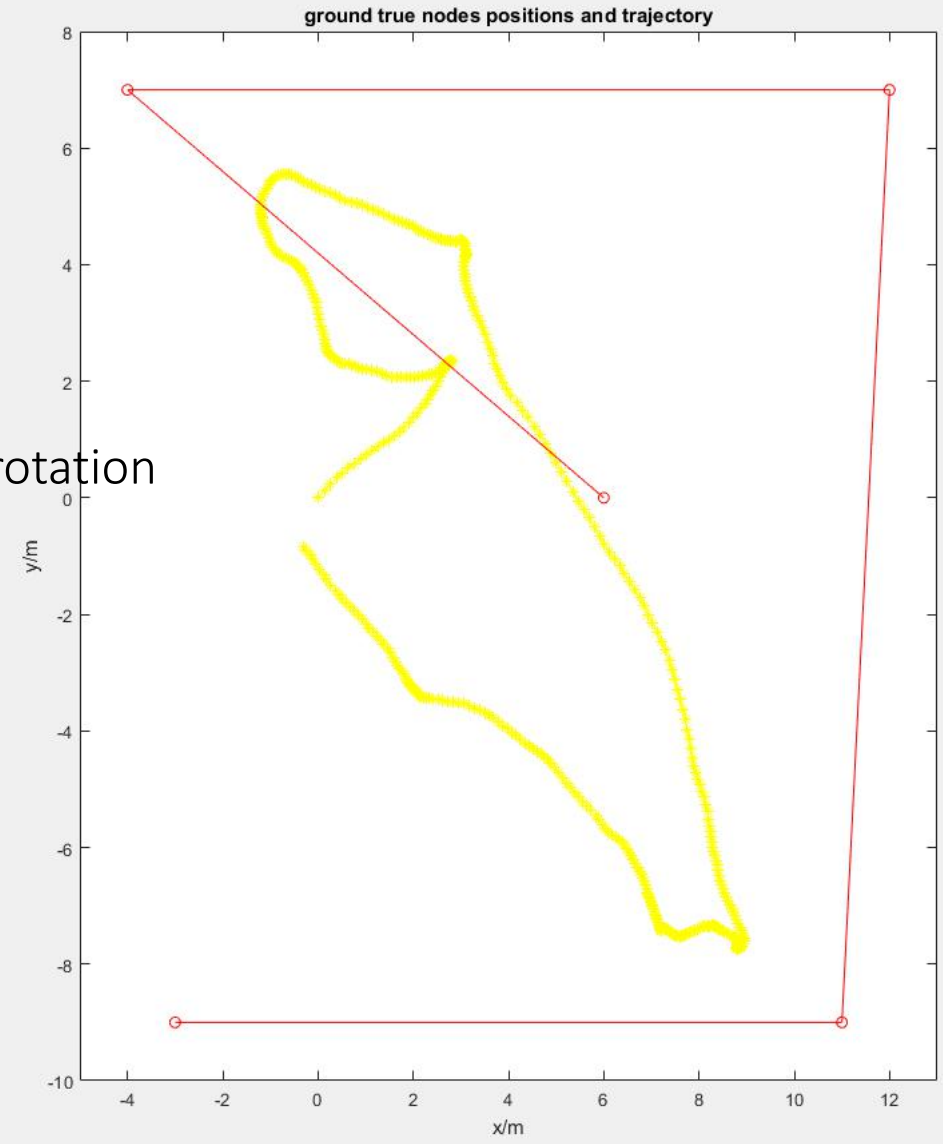
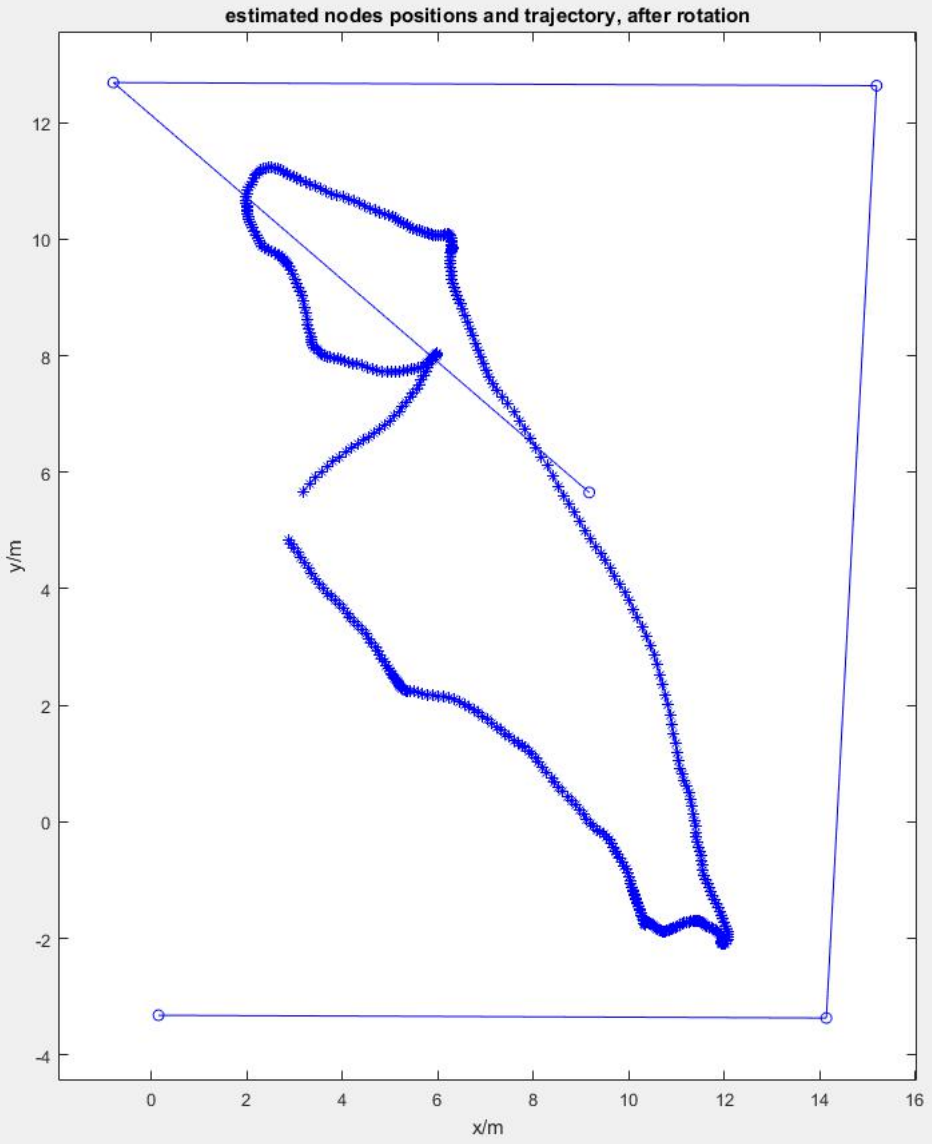
simulation result

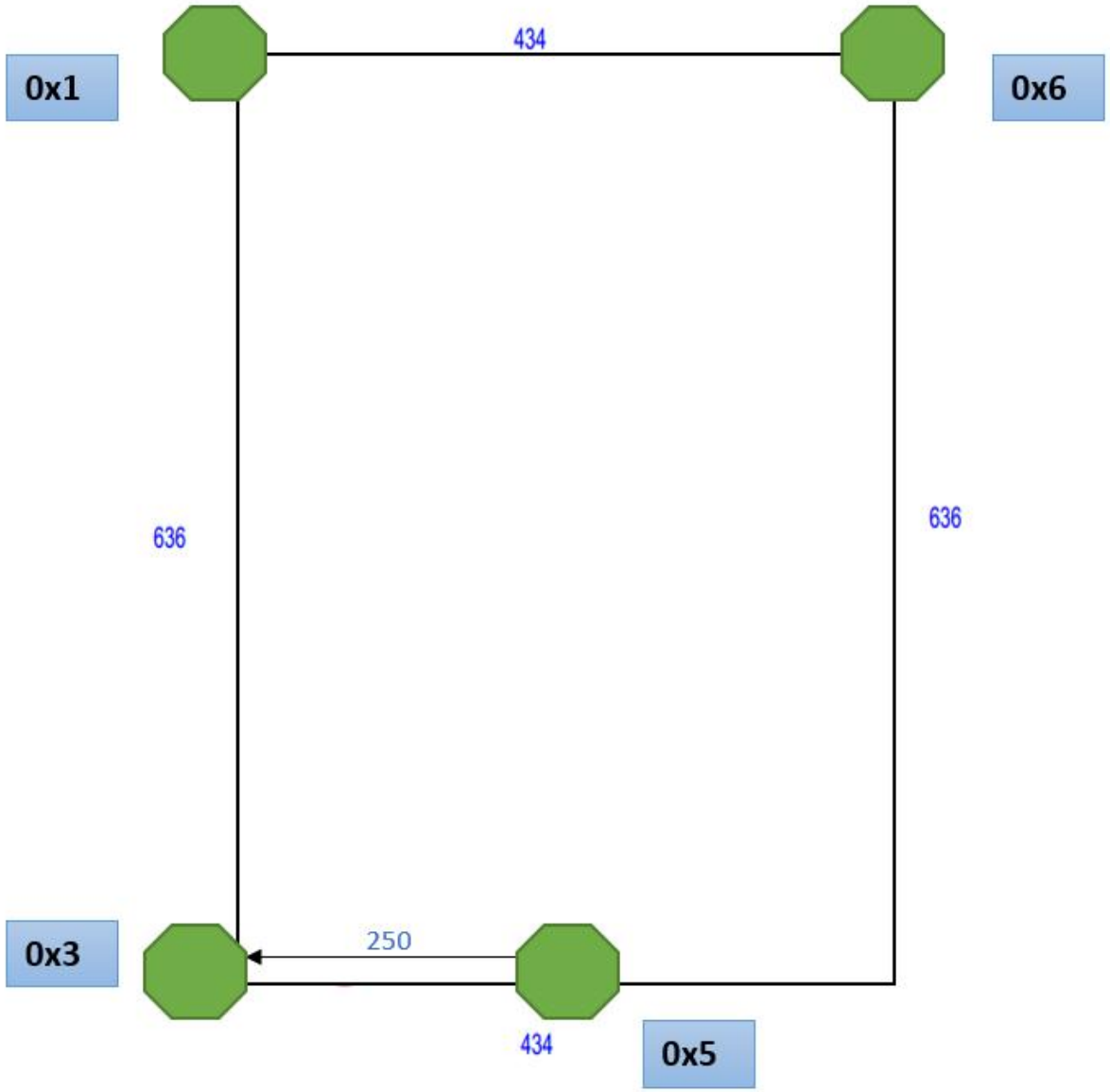


after rotation

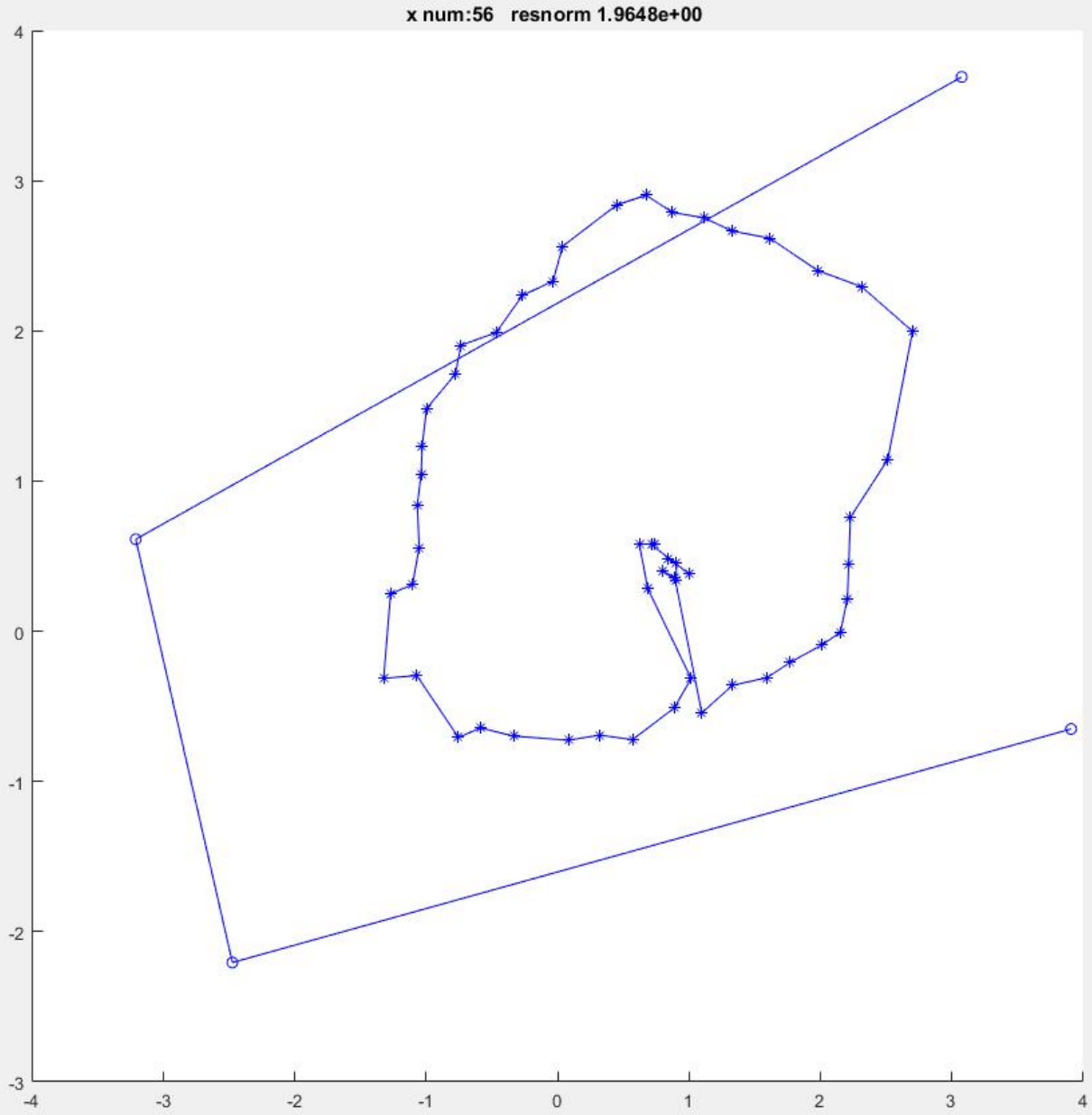




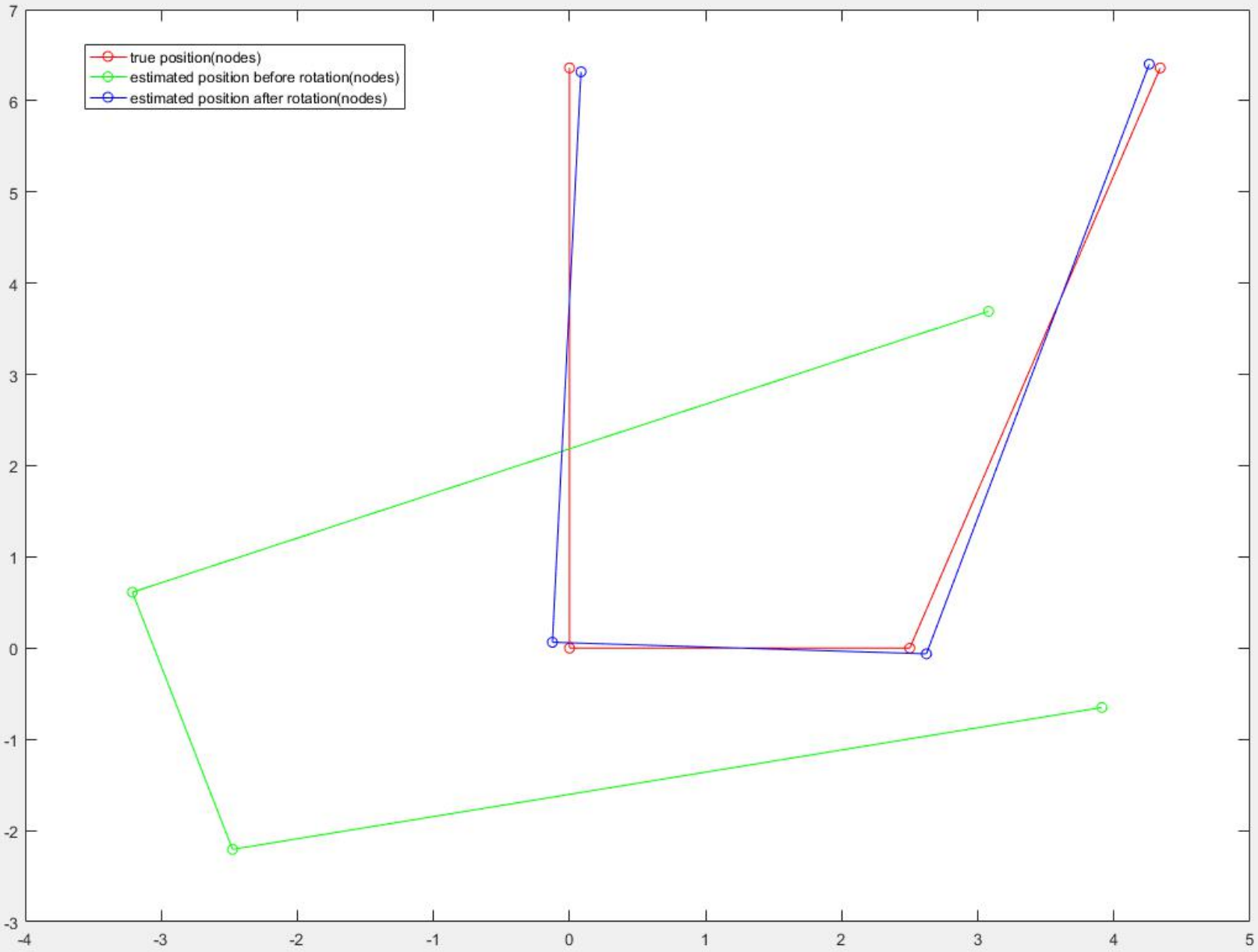
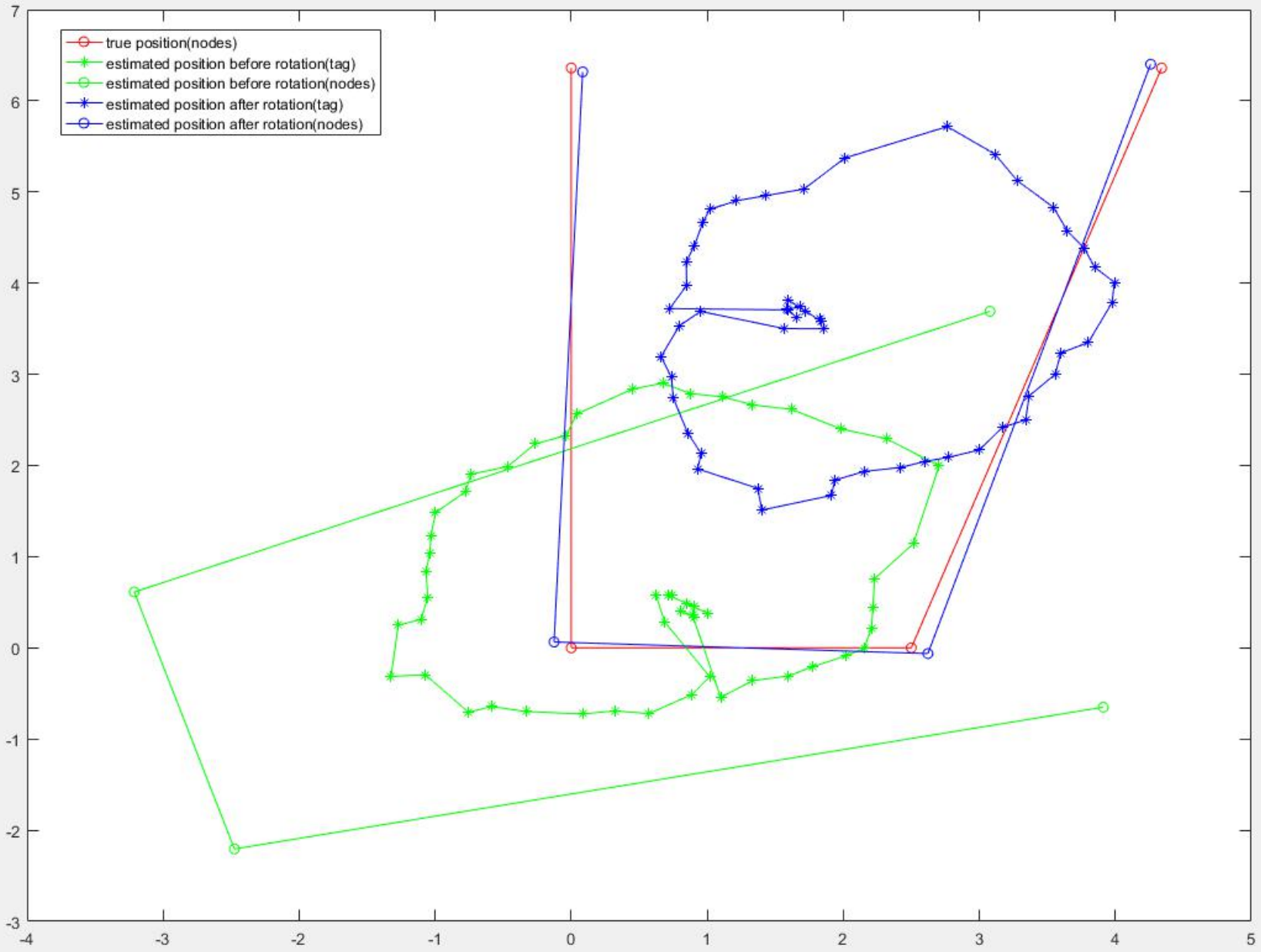
experiment:
true position of the nodes



self_calibration algorithm output with hardware collected data



rotation with only nodes



rotation with tag trajectory and nodes