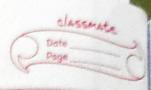
section-B BI Findual & bits/stac ++. h> using namespace std; int main() { ent m,n,k; ainsmssnsk; int almIn]; for(inti=0; ic=m-1; i+t){ for(int)=0; /c=n-1; j+1; for(inti=0; (=m-1; itt)} for (unt)=0; j (=n-1; j+1){

if (alily)==k){

coutecut me"(""");

coutecute """; break; else {
continue;

g
coutce "false";



B.3 of The various sensors are:

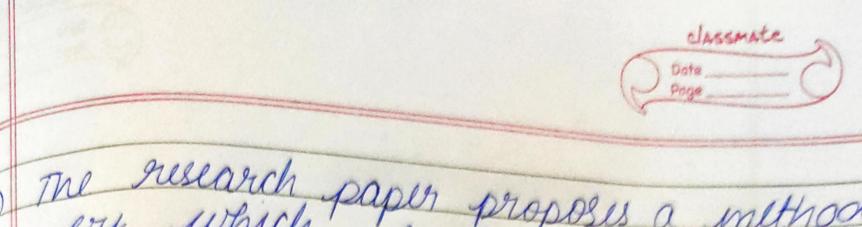
LIDAR: (Light Detection and Ranging) Scanning fre environment with infrared lasers.

CAMERA: captures visual data but does not work well in all weather conditions

INS: (Inertial Navigation System); Detect's car Inysical movements

GPS: To find the physical location of con

sensor fusion: Process of combining
sensor data such that
data has less certainly that
would be possible than individual
sensors.



or the research paper proposes a method by which functing T-shaped & the wehich using LIDAR point cloud

· Because GPS, INS, GIS are not reliable

It uses distance function vorsus angle of each beam to find intersections.

I thenk this is quite innovative because using openCV in such situations is very hard. This method has its flaws. It is relatively expensive and harder to repair if any error occurs.