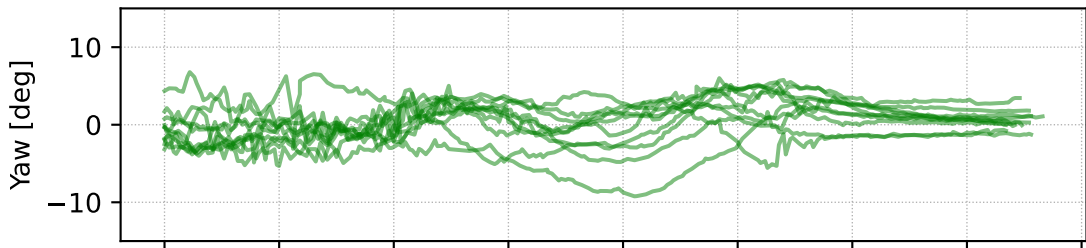


Actual trajectory

Yaw (Without compensation)



Yaw (With compensation)

