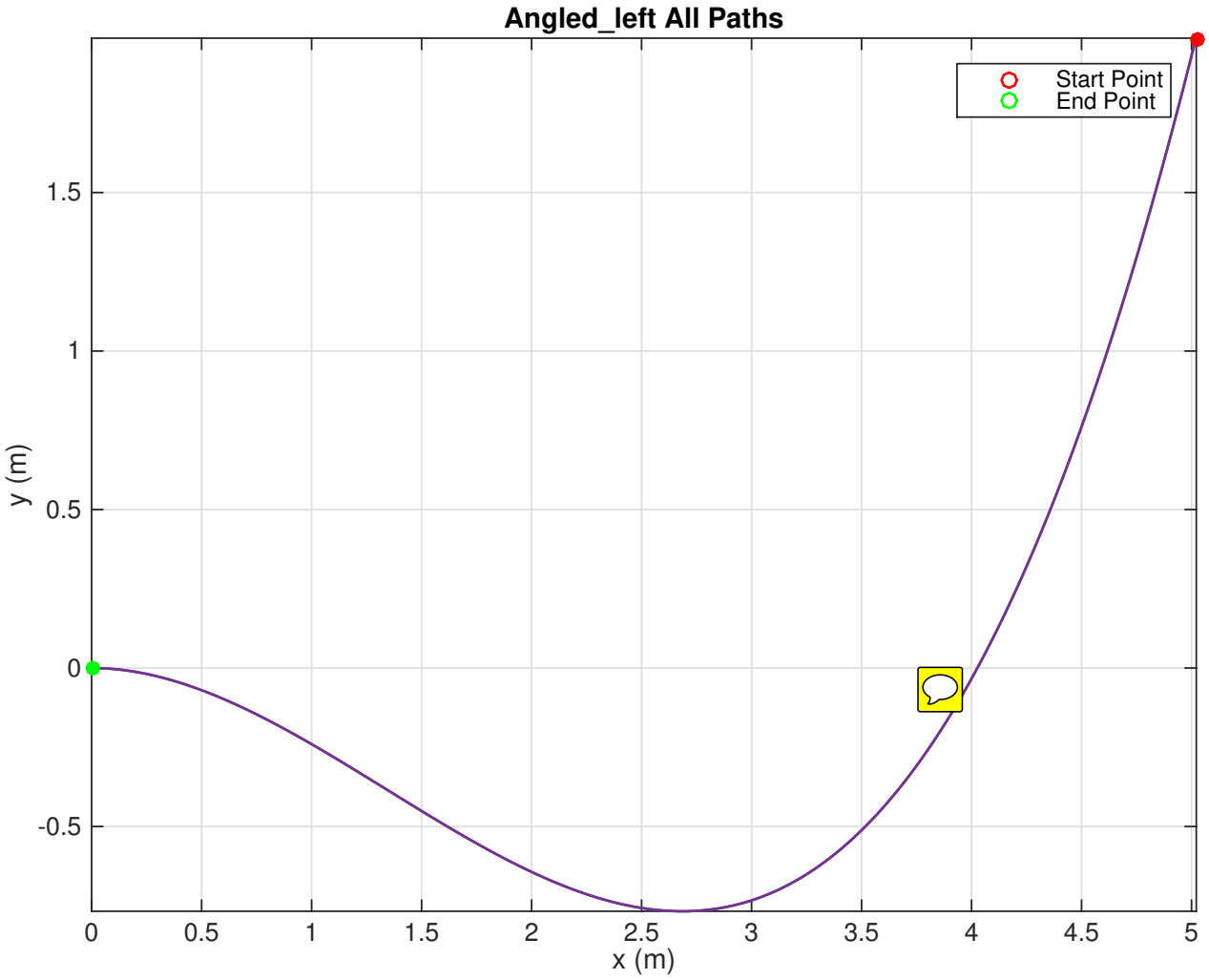
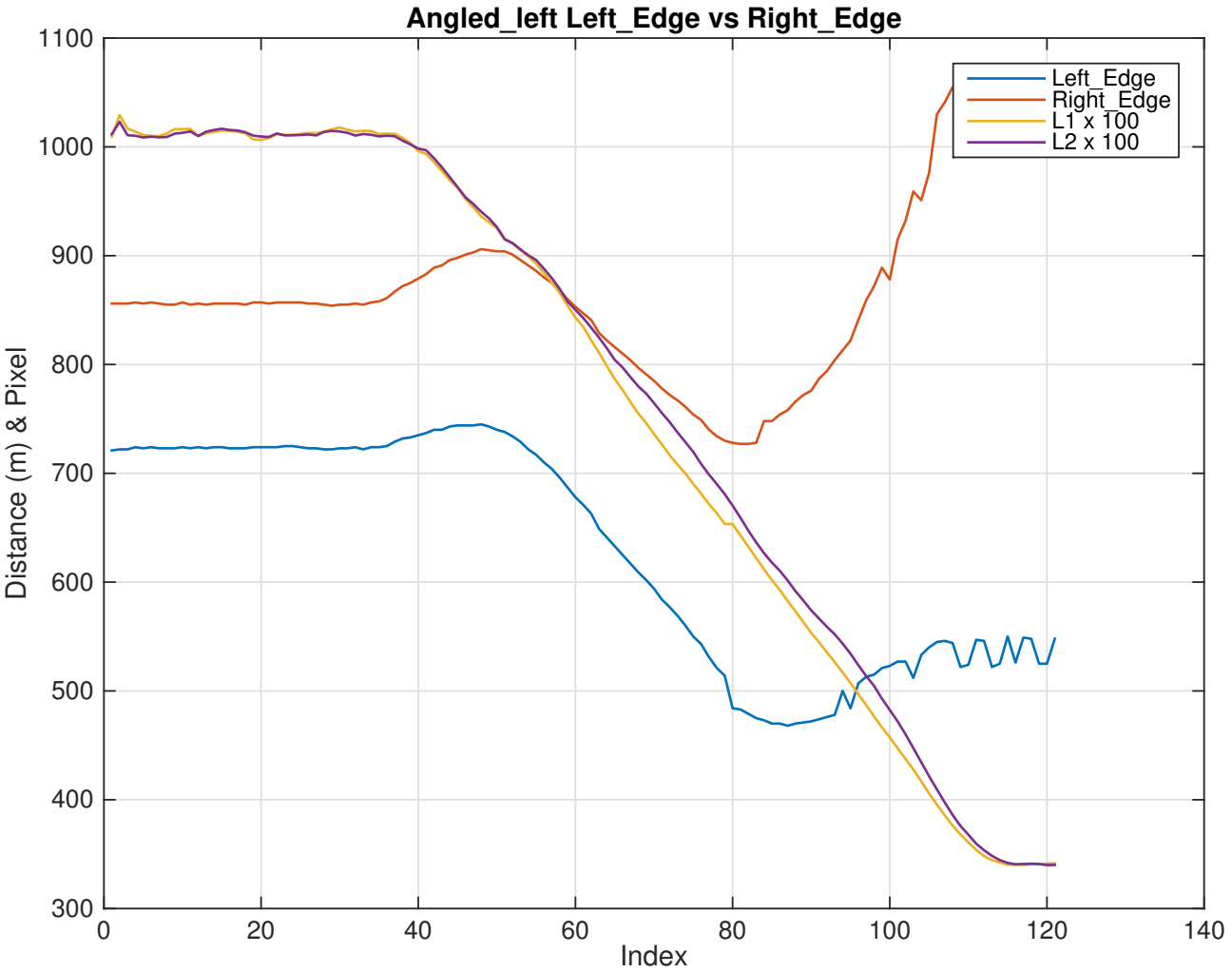
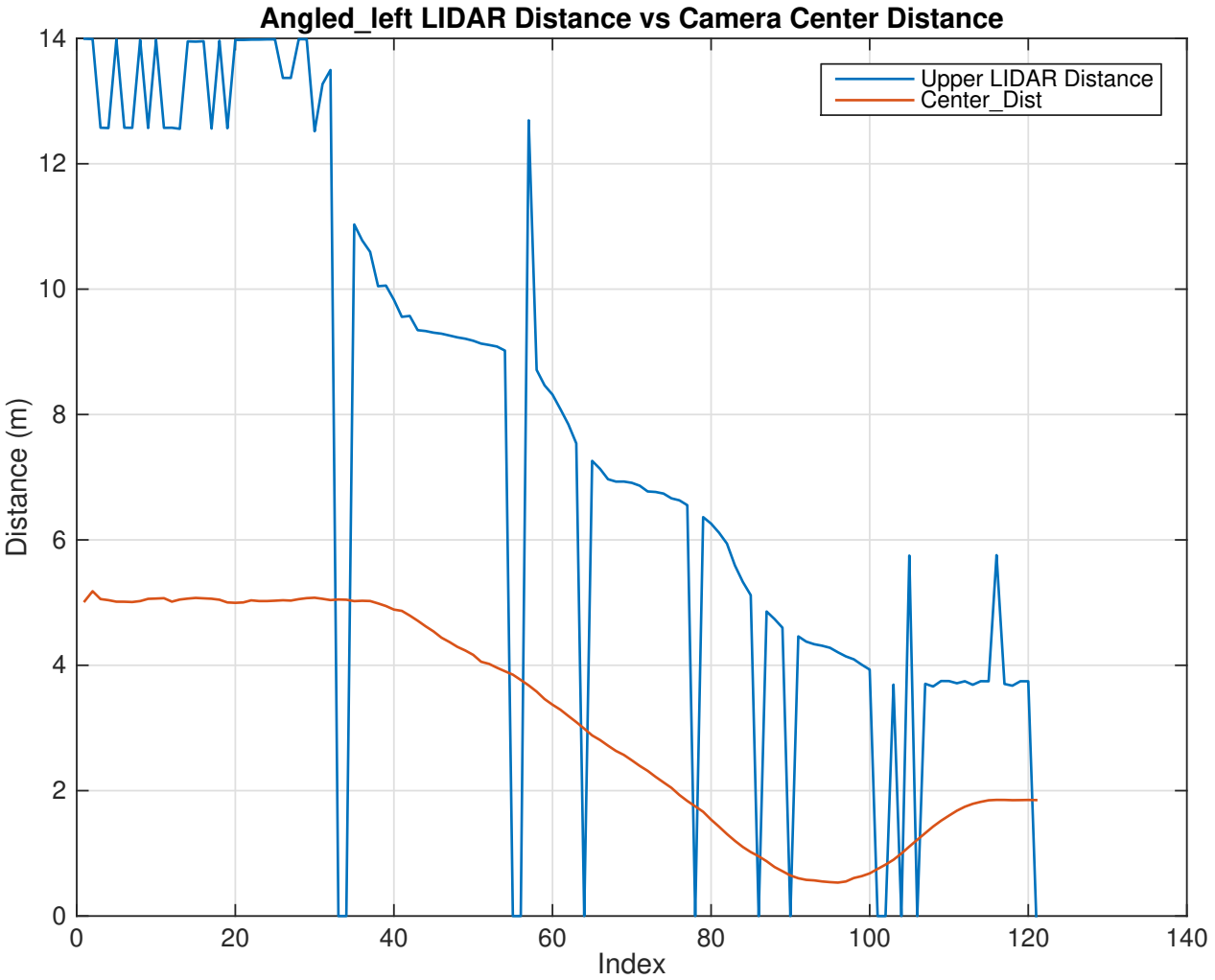
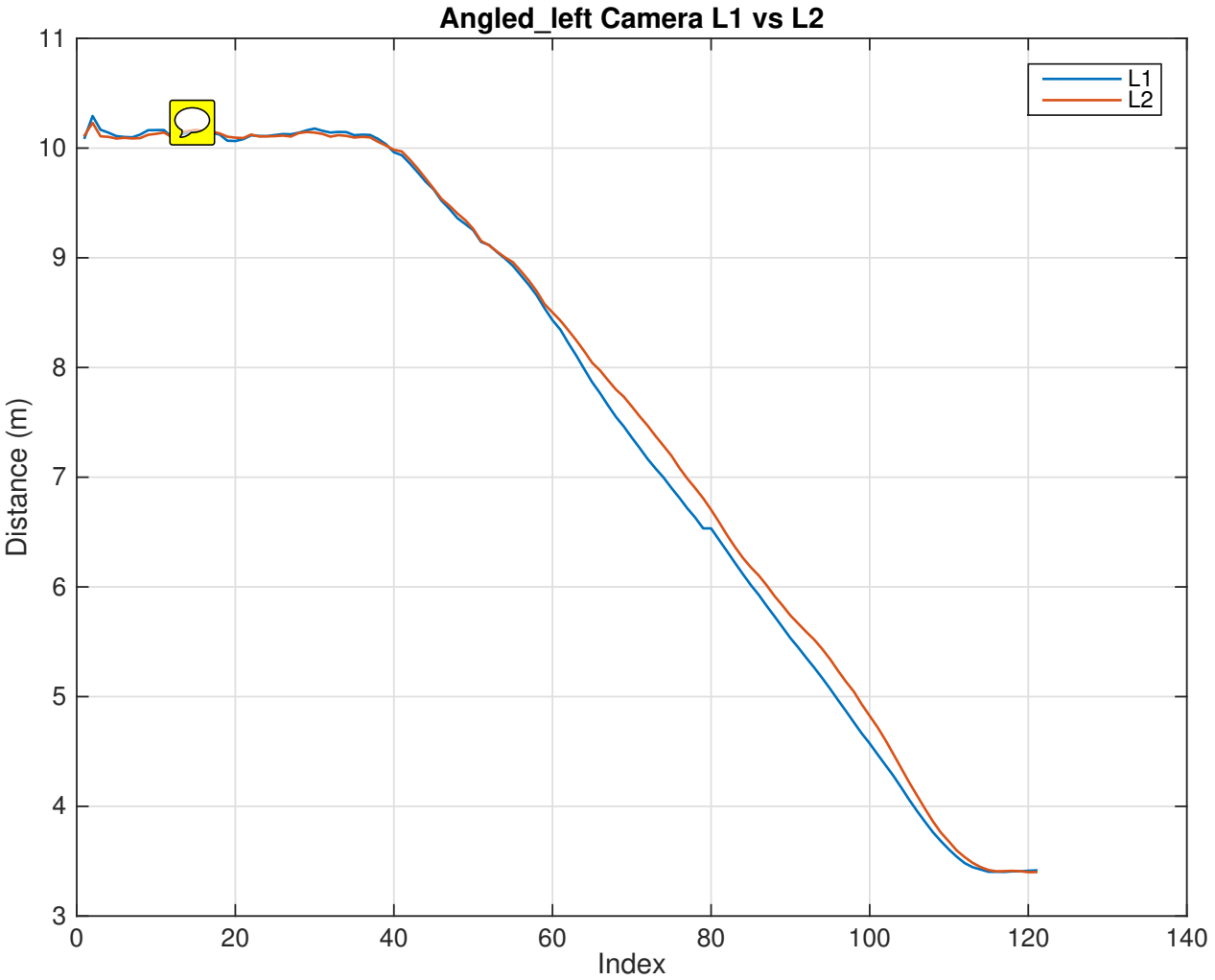
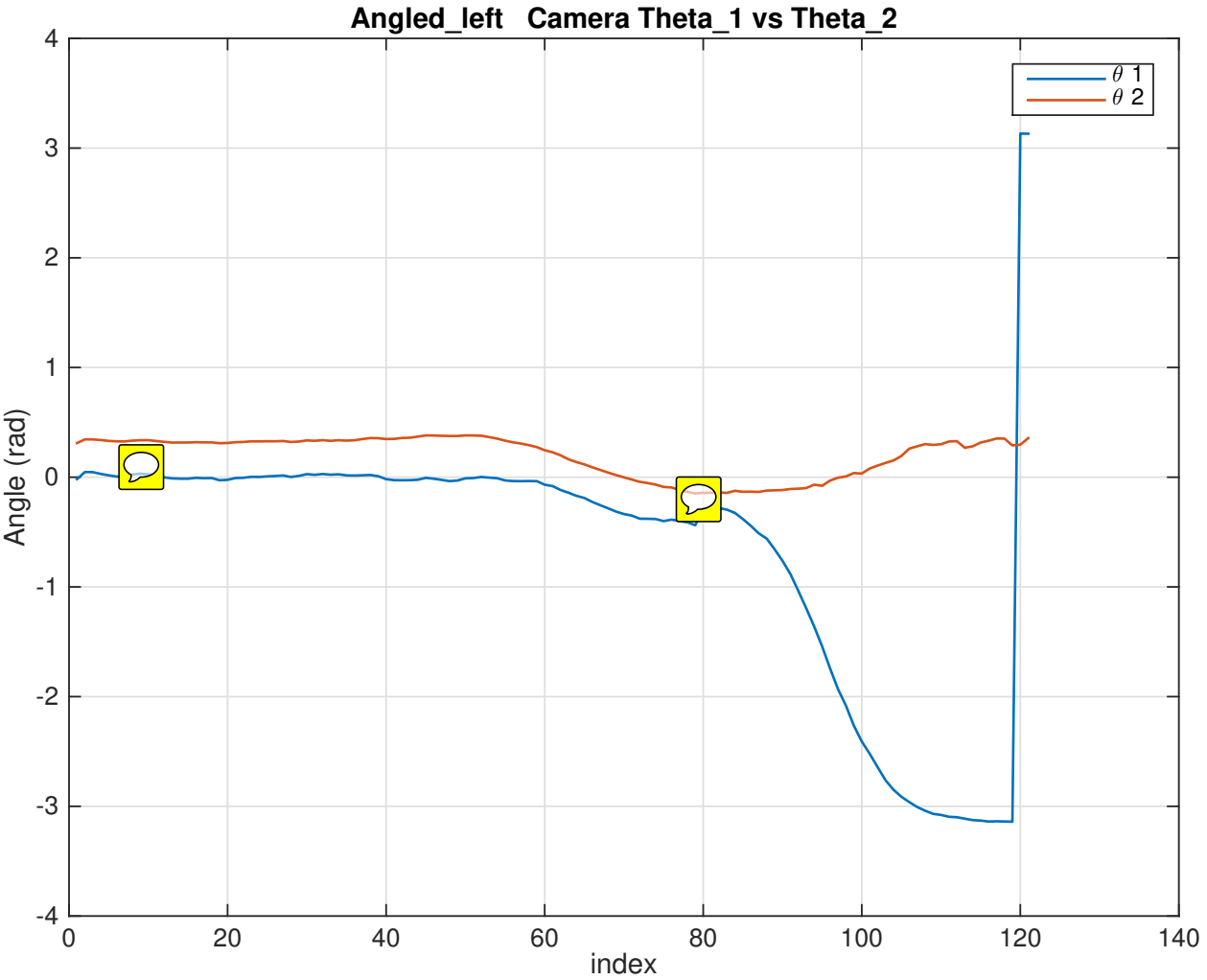

Angled_left All Paths
Start Point
End Point
1.5
1
0.5
0
-0.5
y (m)
0
0.5
1
1.5
2
2.5
3
3.5
4
4.5
5
x (m)

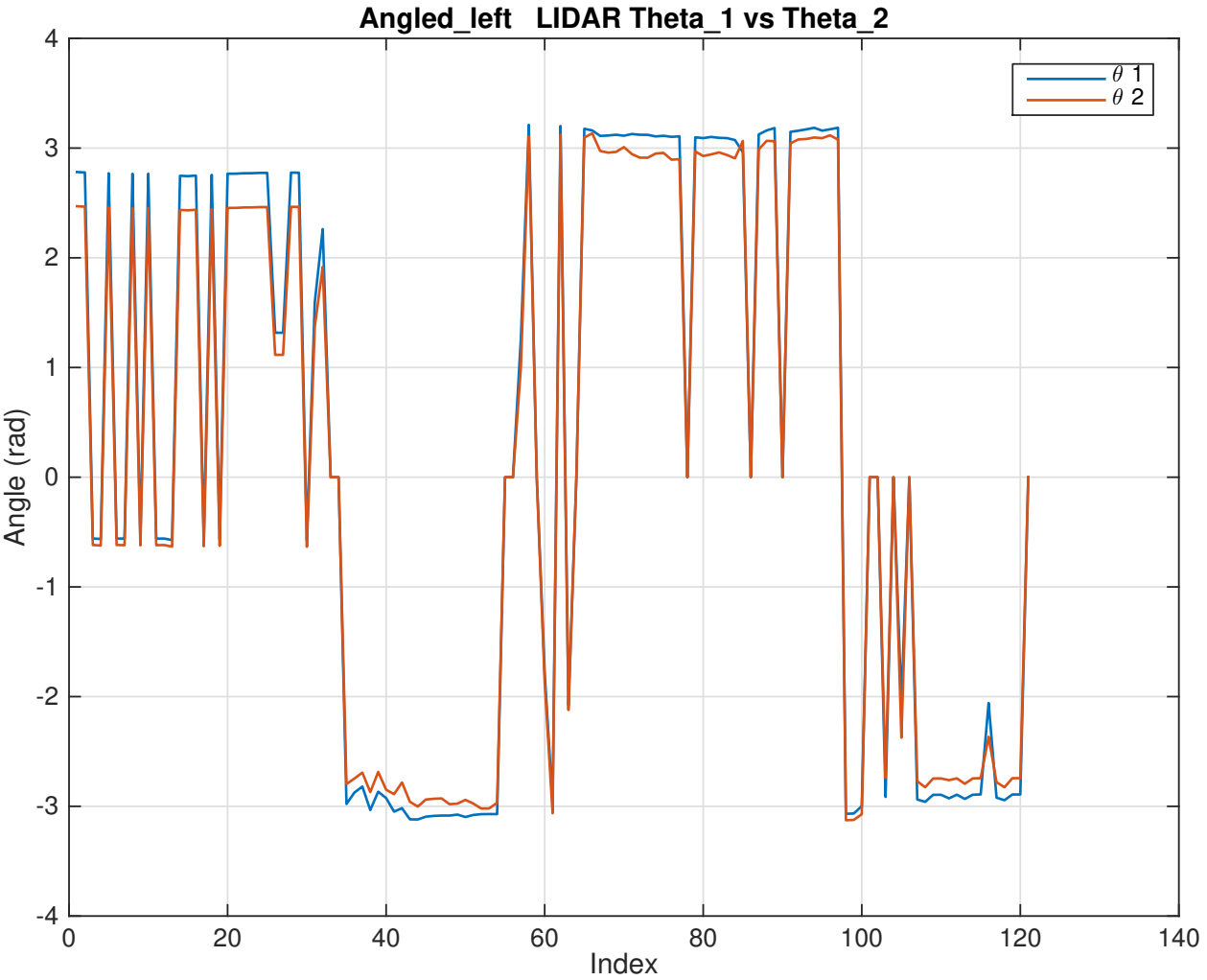
Number_Of_Unique_Paths	King_Pin_Detected
17	false

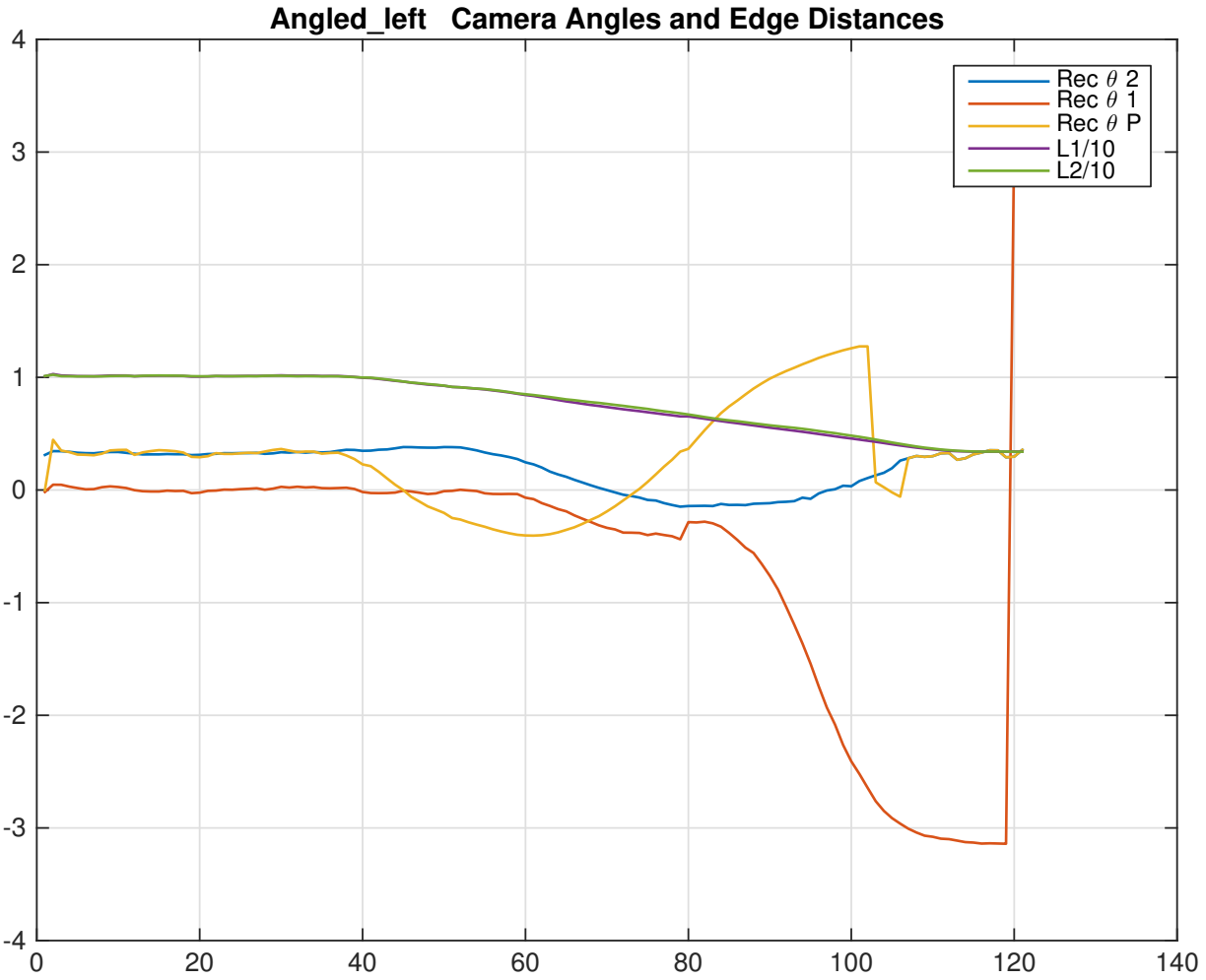

Angled_left Left_Edge vs Right_Edge
Left_Edge
Right_Edge
L1 x 100
L2 x 100
Distance (m) & Pixel
Index
1100
1000
900
800
700
600
500
400
300
0
20
40
60
80
100
120
140

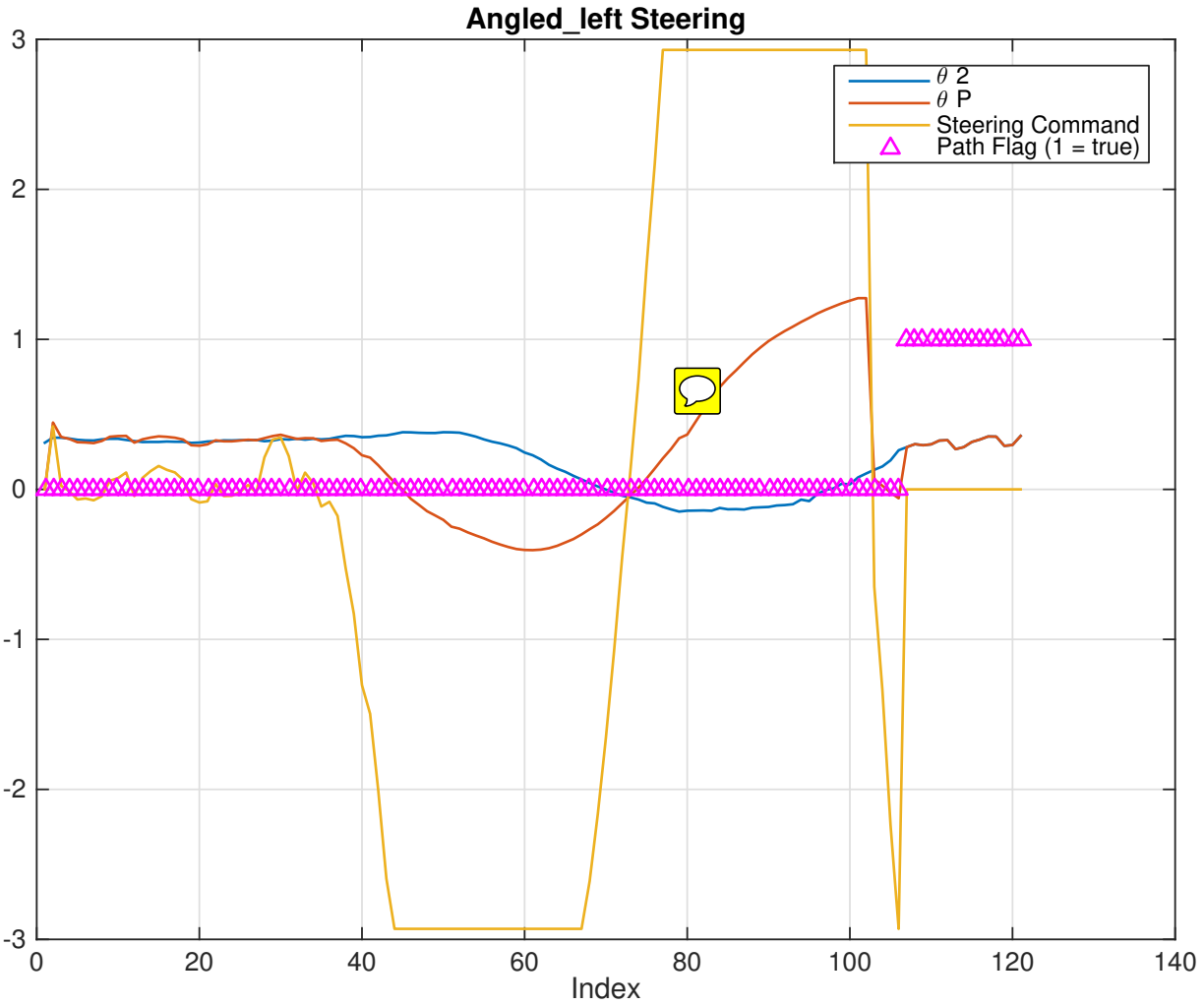

Angled_left LIDAR Distance vs Camera Center Distance
Upper LIDAR Distance
Center_Dist
Distance (m)
Index
0
2
4
6
8
10
12
14
0
20
40
60
80
100
120
140

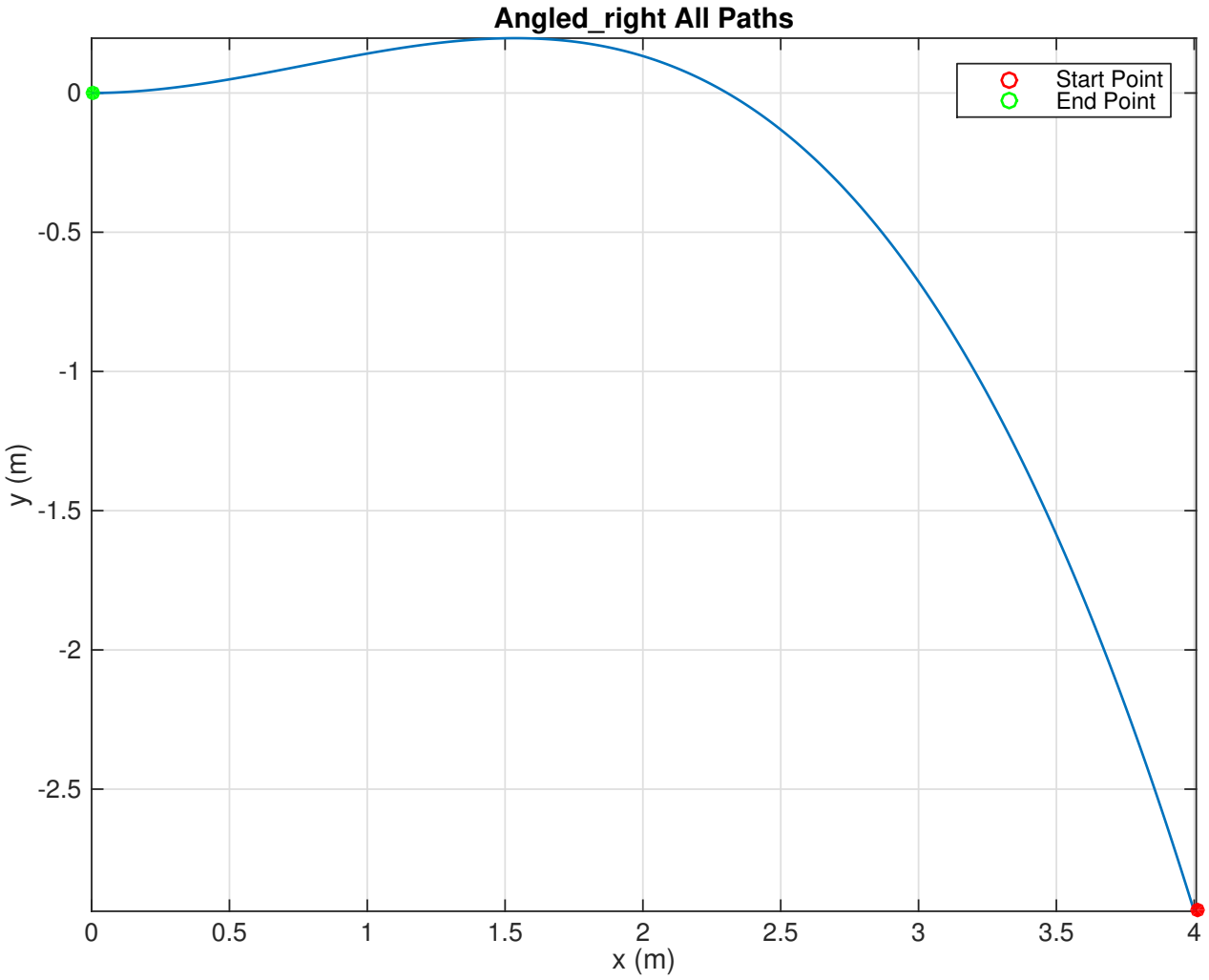

Angled_left Camera L1 vs L2
L1
L2
Distance (m)
Index
11
10
9
8
7
6
5
4
3
0
20
40
60
80
100
120
140


Angled_left Camera Theta_1 vs Theta_2
θ 1
θ 2
Angle (rad)
index
4
3
2
1
0
-1
-2
-3
-4
0
20
40
60
80
100
120
140

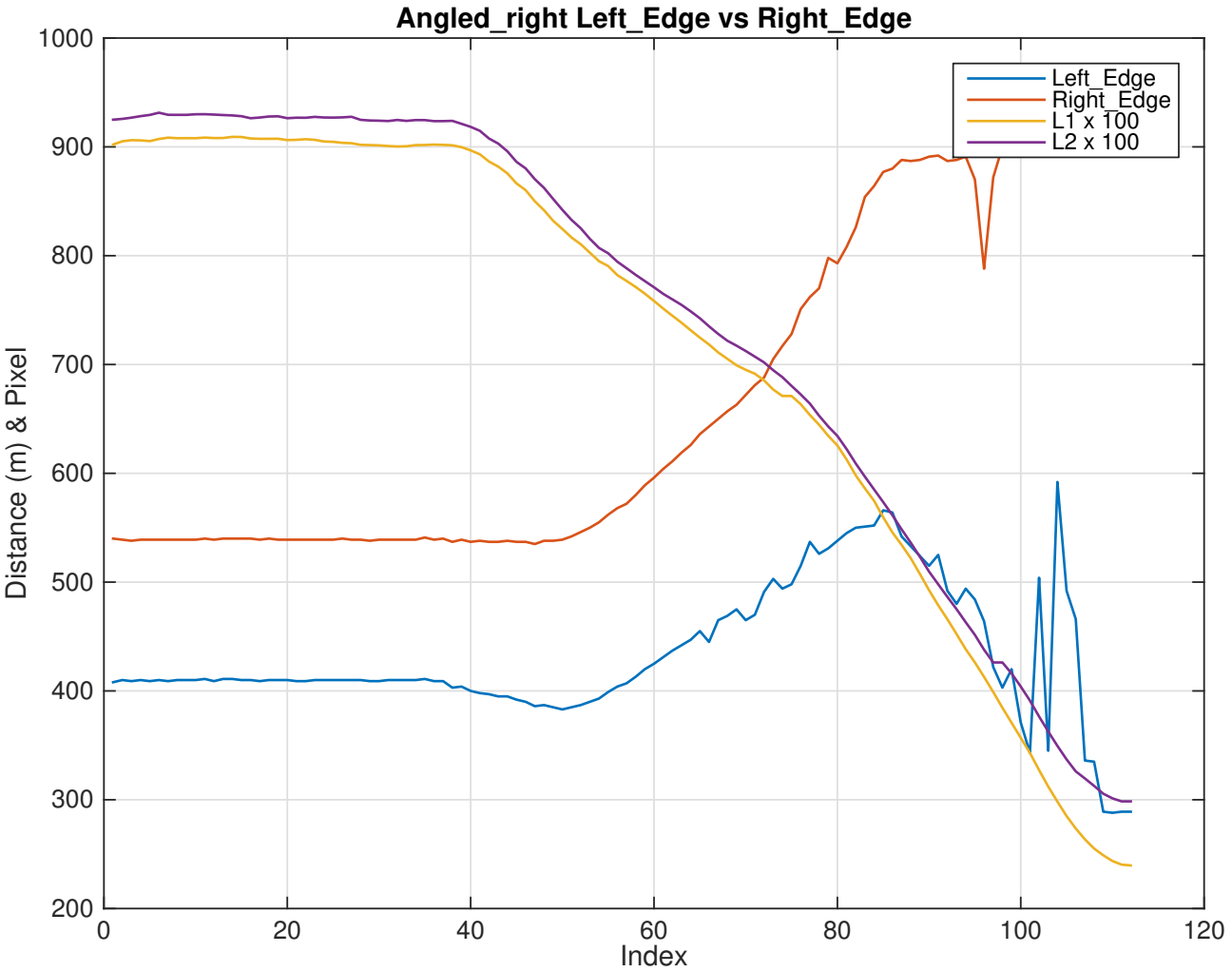

Angled_left LIDAR Theta_1 vs Theta_2
θ 1
θ 2
Angle (rad)
Index
4
3
2
1
0
-1
-2
-3
-4
0
20
40
60
80
100
120
140

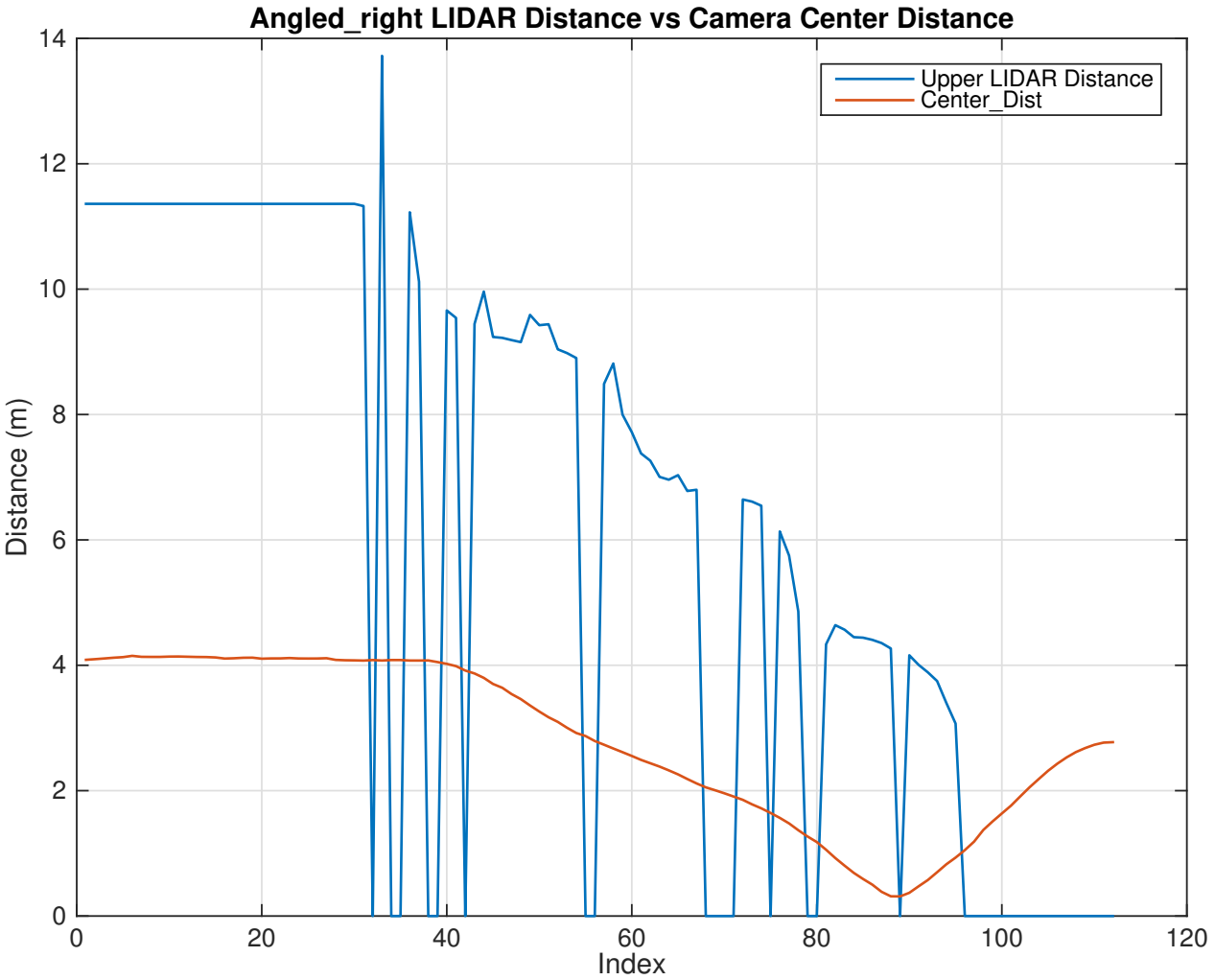

Angled_left Camera Angles and Edge Distances
Rec θ 2
Rec θ 1
Rec θ P
L1/10
L2/10
4
3
2
1
0
-1
-2
-3
-4
0
20
40
60
80
100
120
140

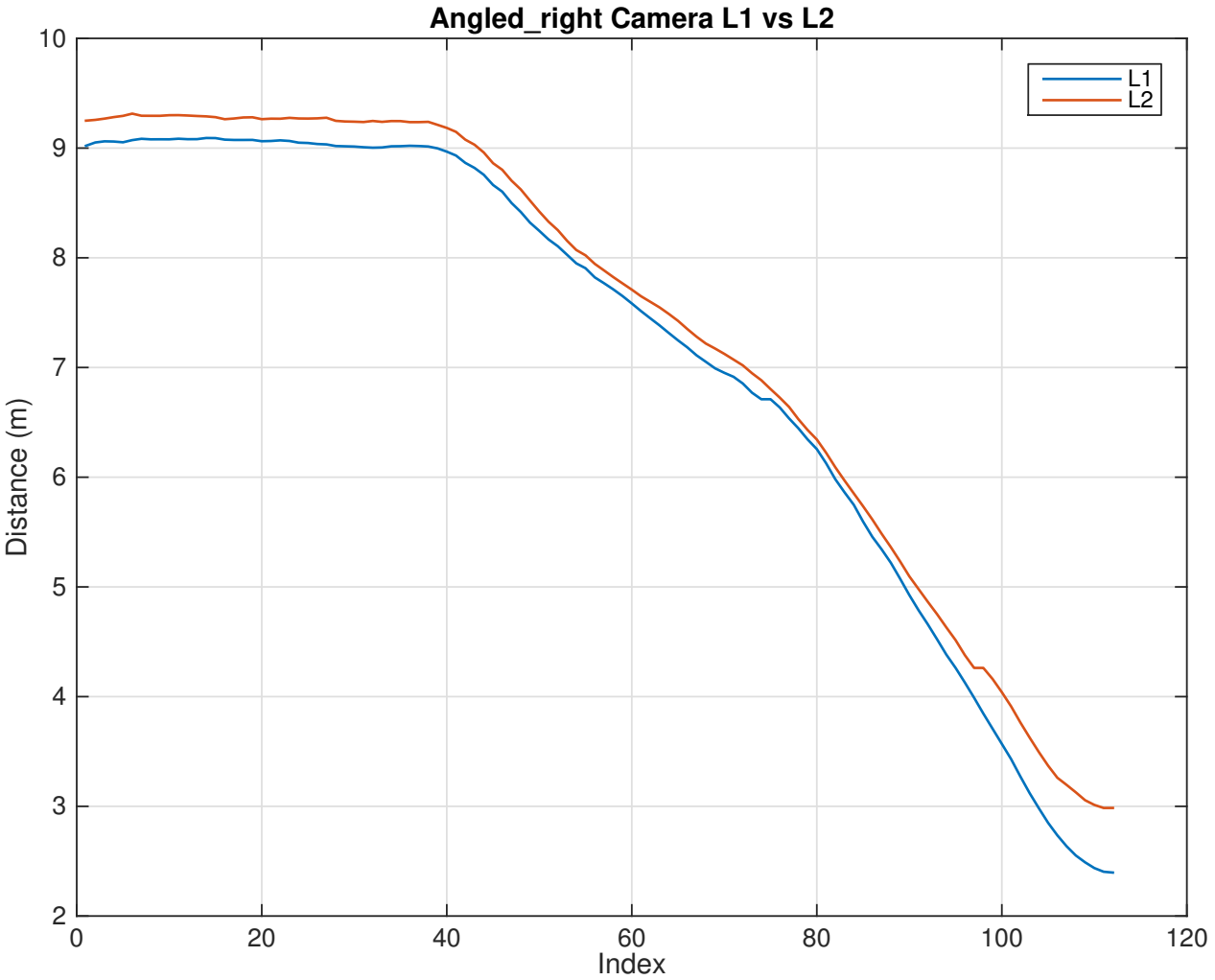

Angled_left Steering
θ 2
θ P
Steering Command
Path Flag (1 = true)
3
2
1
0
-1
-2
-3
0
20
40
60
80
100
120
140
Index

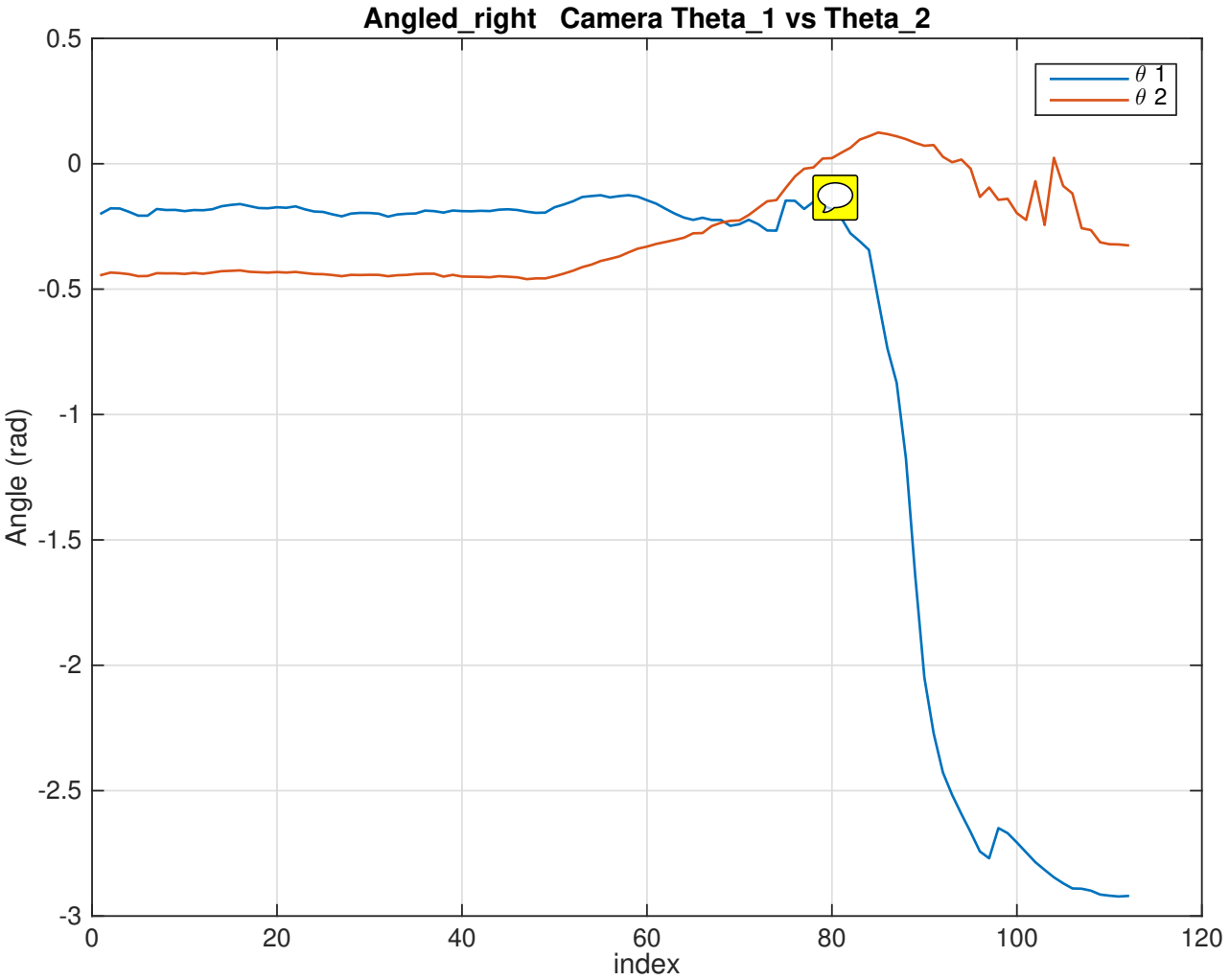

Angled_right All Paths
Start Point
End Point
0
-0.5
-1
-1.5
-2
-2.5
y (m)
0
0.5
1
1.5
2
2.5
3
3.5
4
x (m)

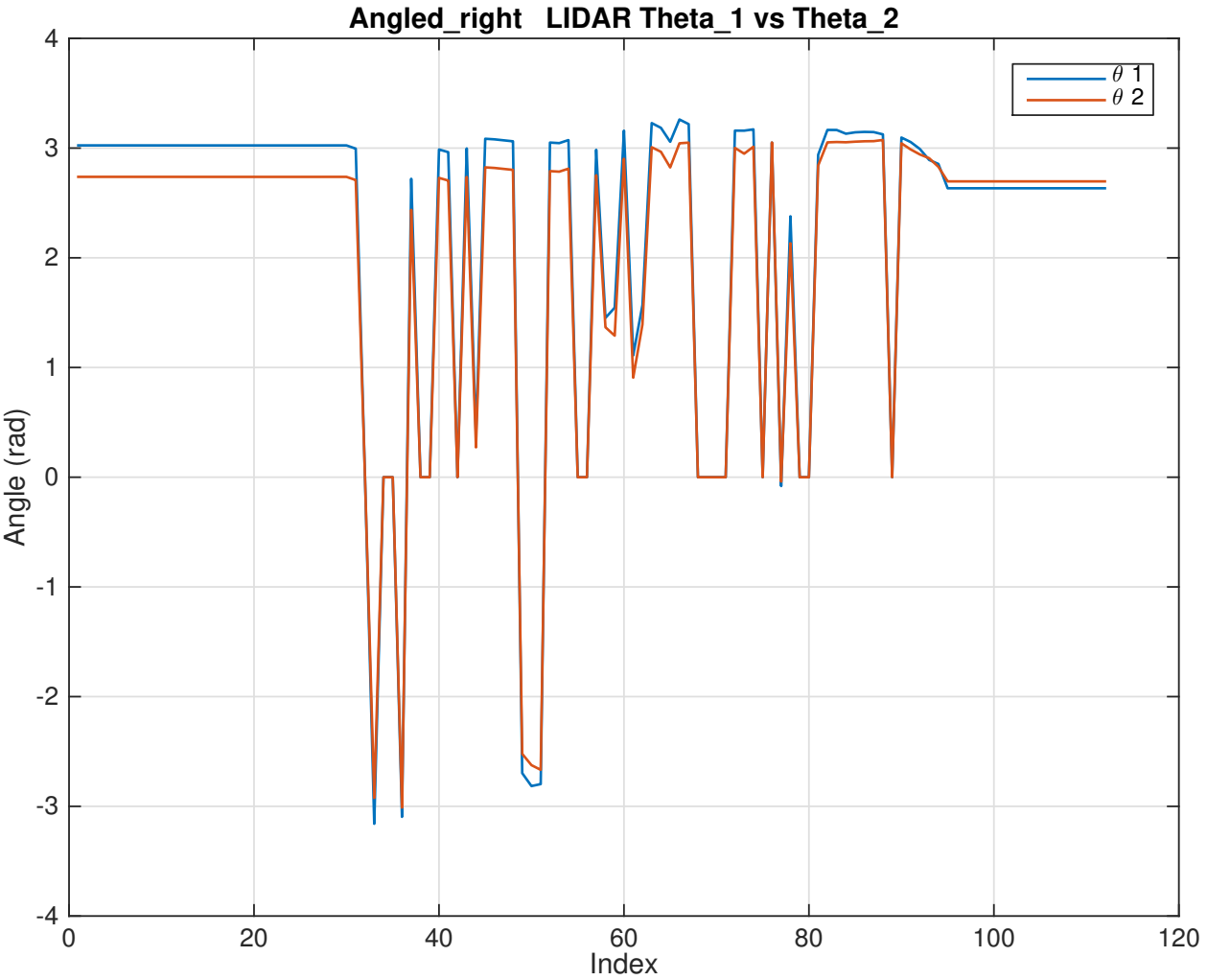
Number_Of_Unique_Paths	King_Pin_Detected
1	false

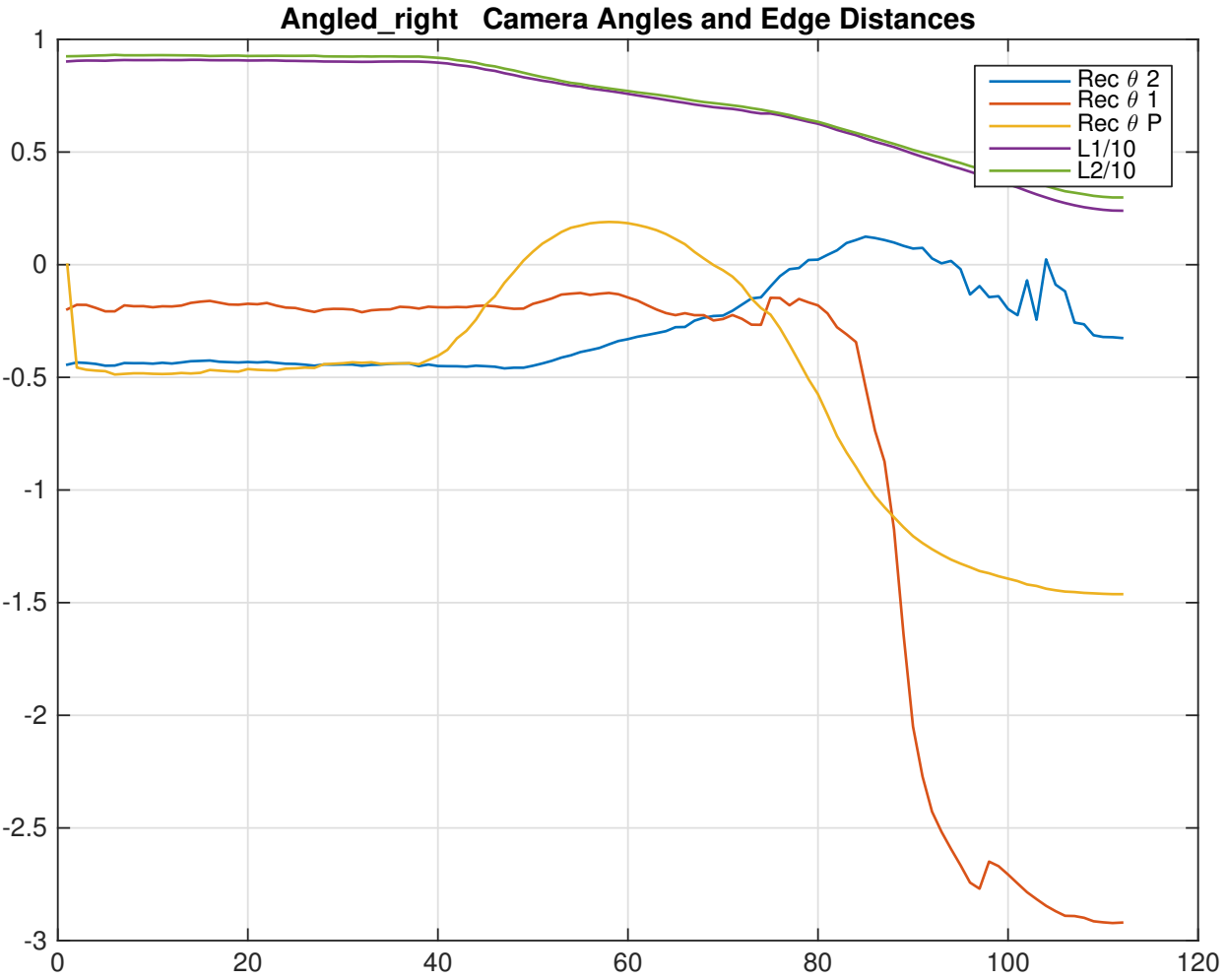

Angled_right Left_Edge vs Right_Edge
Left_Edge
Right_Edge
L1 x 100
L2 x 100
Distance (m) & Pixel
Index
1000
900
800
700
600
500
400
300
200
0
20
40
60
80
100
120

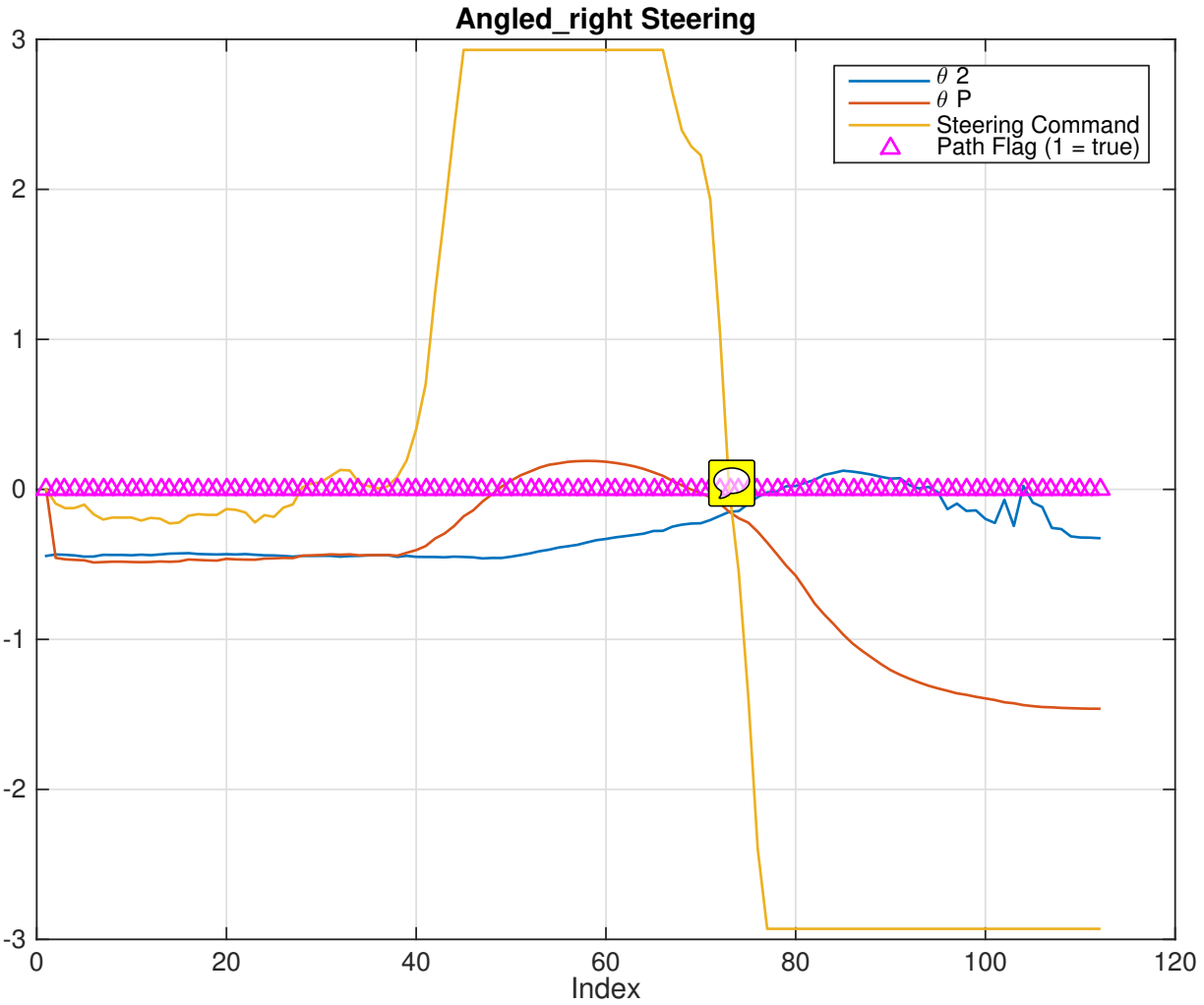

Angled_right LIDAR Distance vs Camera Center Distance
Upper LIDAR Distance
Center_Dist
Distance (m)
Index
0
2
4
6
8
10
12
14
0
20
40
60
80
100
120

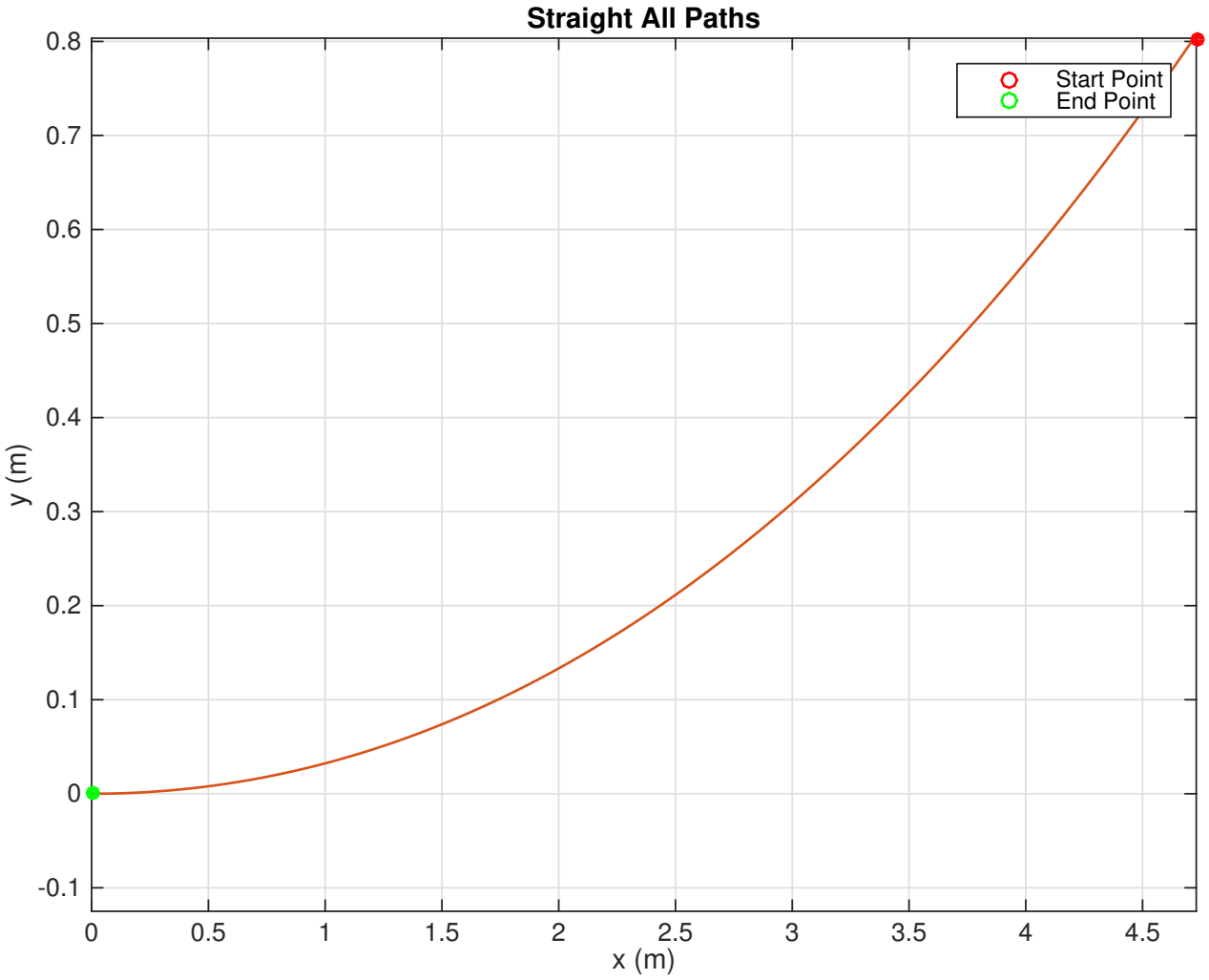

Angled_right Camera L1 vs L2
L1
L2
Distance (m)
Index
10
9
8
7
6
5
4
3
2
0
20
40
60
80
100
120


Angled_right Camera Theta_1 vs Theta_2
θ 1
θ 2
Angle (rad)
index
0.5
0
-0.5
-1
-1.5
-2
-2.5
-3
0
20
40
60
80
100
120

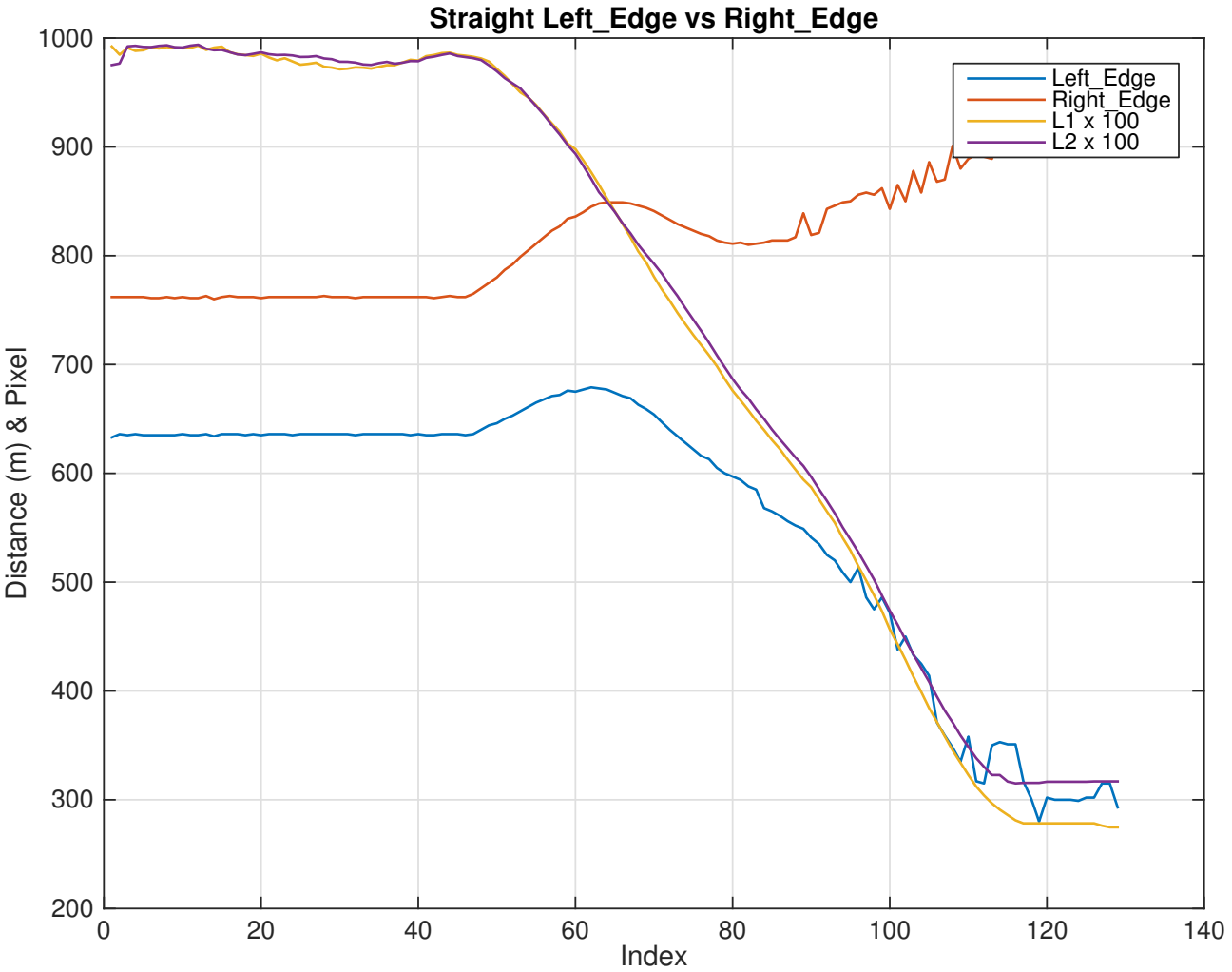

Angled_right LIDAR Theta_1 vs Theta_2
θ 1
θ 2
Angle (rad)
Index
4
3
2
1
0
-1
-2
-3
-4
0
20
40
60
80
100
120

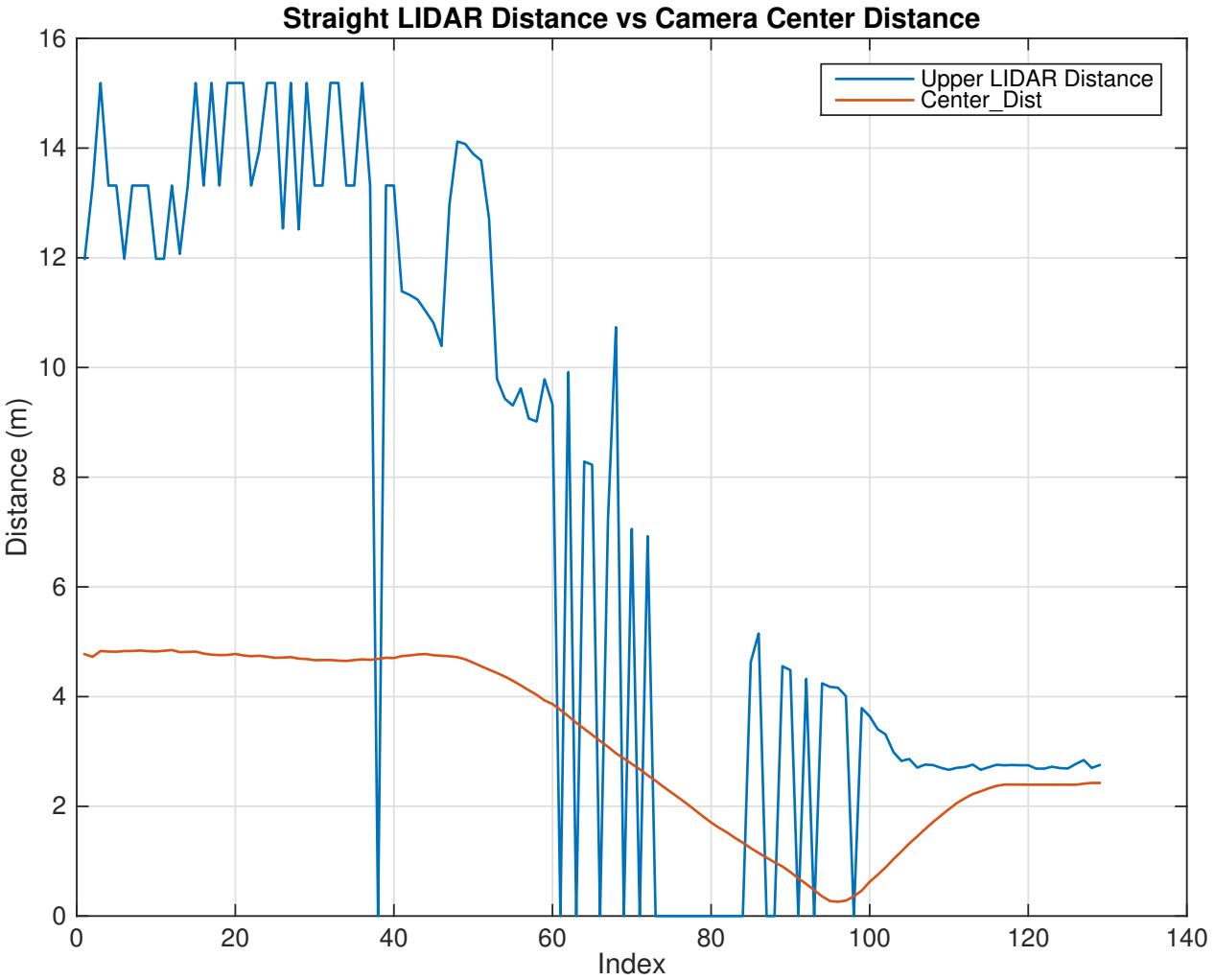

Angled_right Camera Angles and Edge Distances
Rec θ 2
Rec θ 1
Rec θ P
L1/10
L2/10
1
0.5
0
-0.5
-1
-1.5
-2
-2.5
-3
0
20
40
60
80
100
120

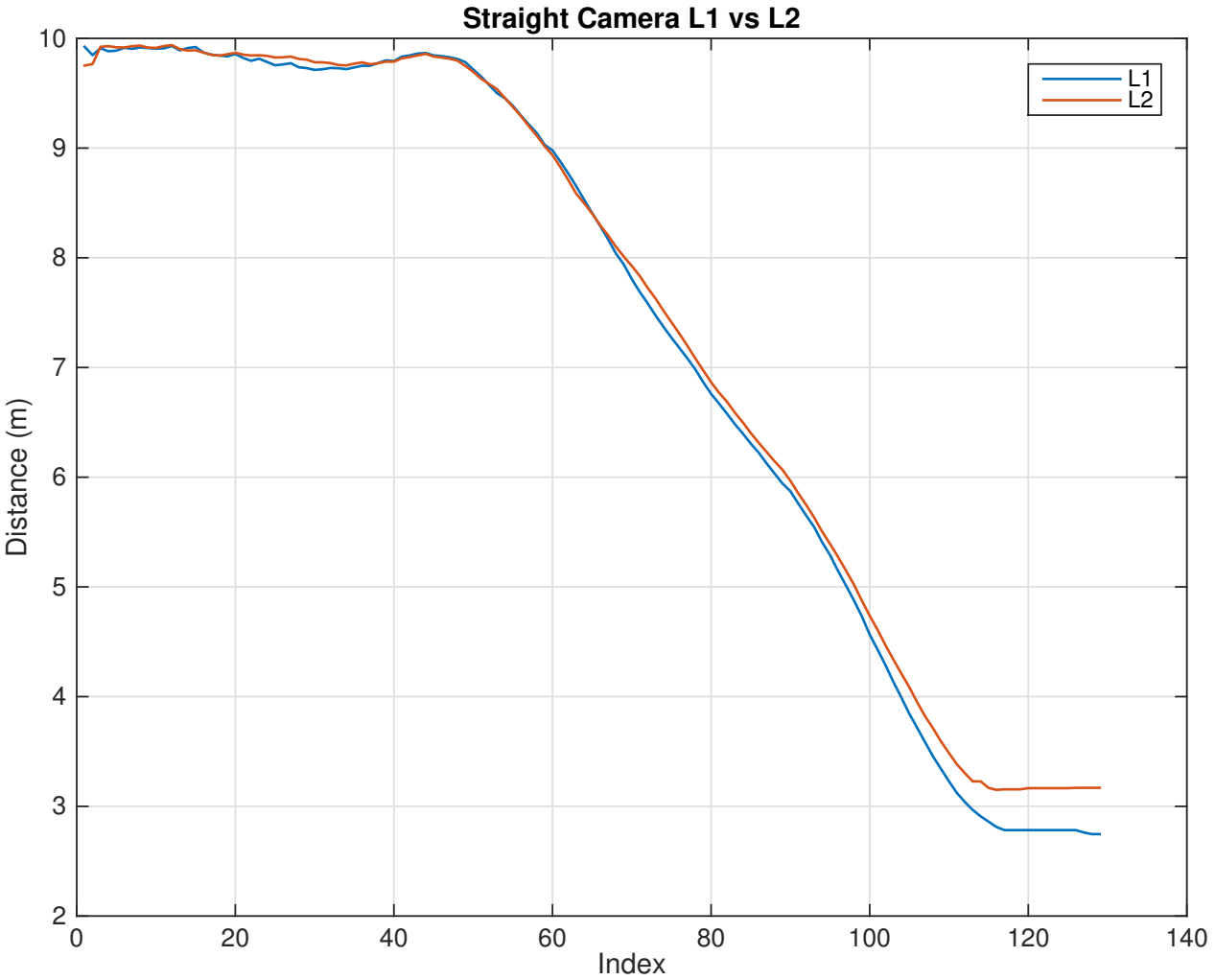

Angled_right Steering
θ 2
θ P
Steering Command
Path Flag (1 = true)
3
2
1
0
-1
-2
-3
0
20
40
60
80
100
120
Index

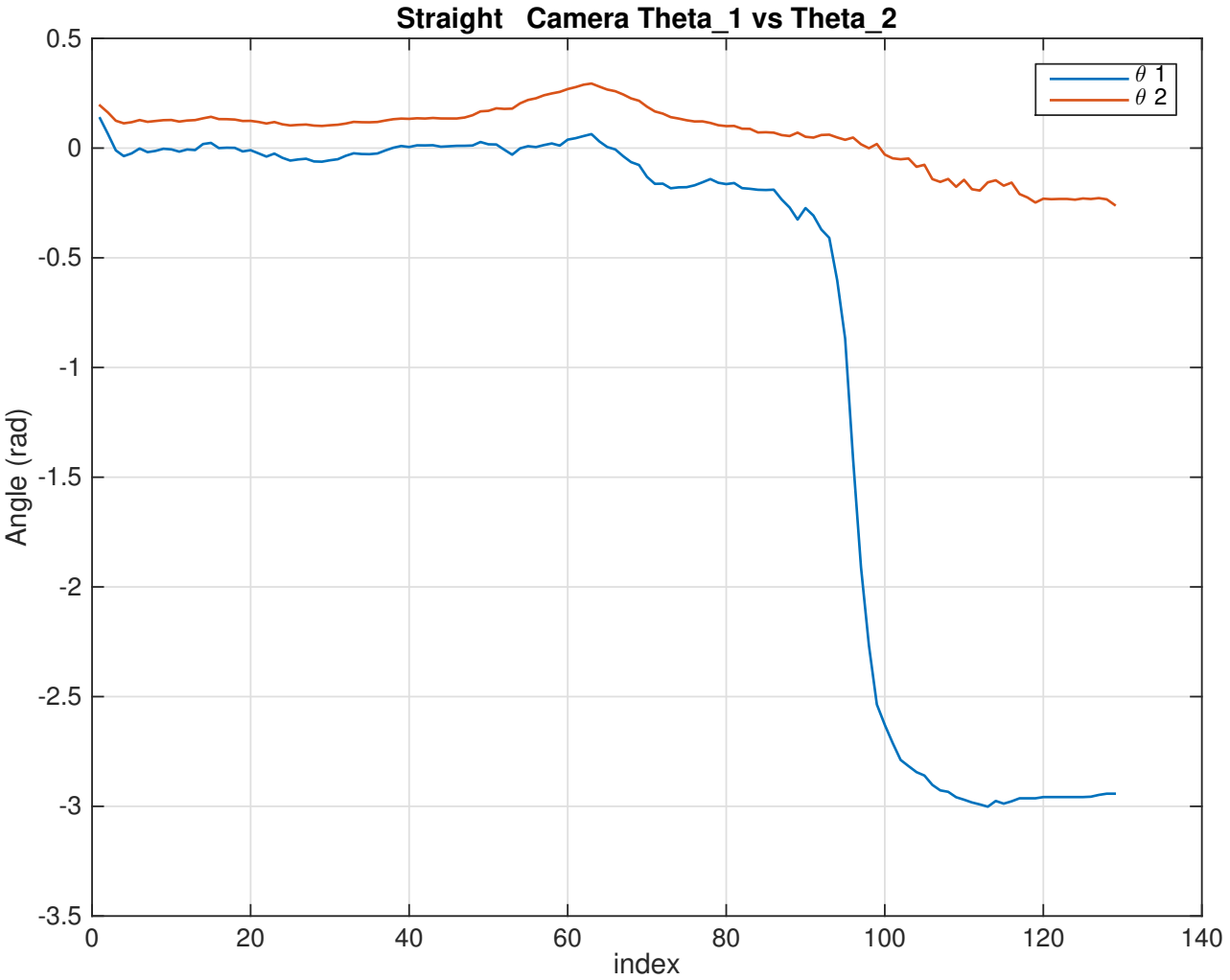

Straight All Paths
Start Point
End Point
y (m)
x (m)
0.8
0.7
0.6
0.5
0.4
0.3
0.2
0.1
0
-0.1
0
0.5
1
1.5
2
2.5
3
3.5
4
4.5

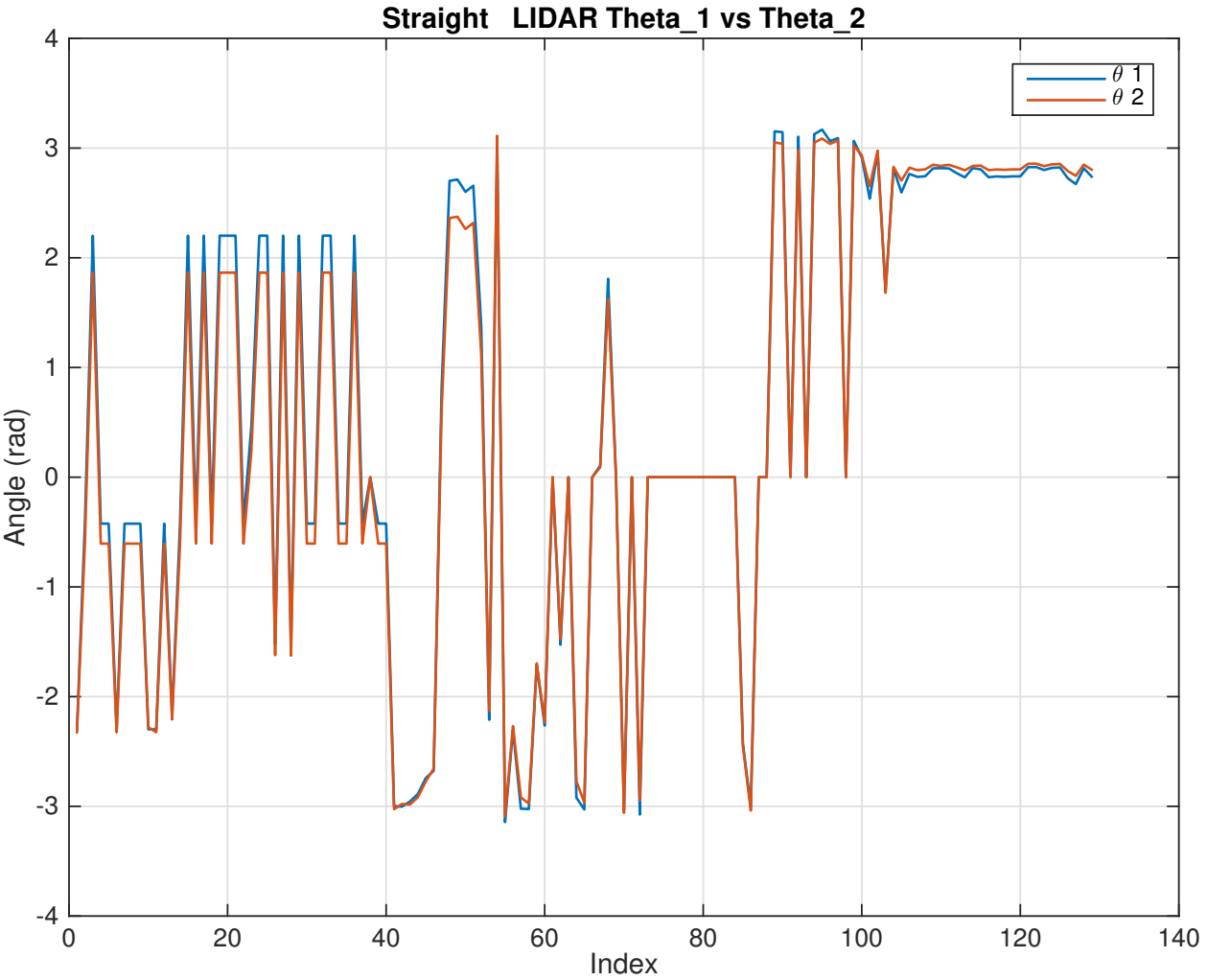
Number_Of_Unique_Paths	King_Pin_Detected
2	false

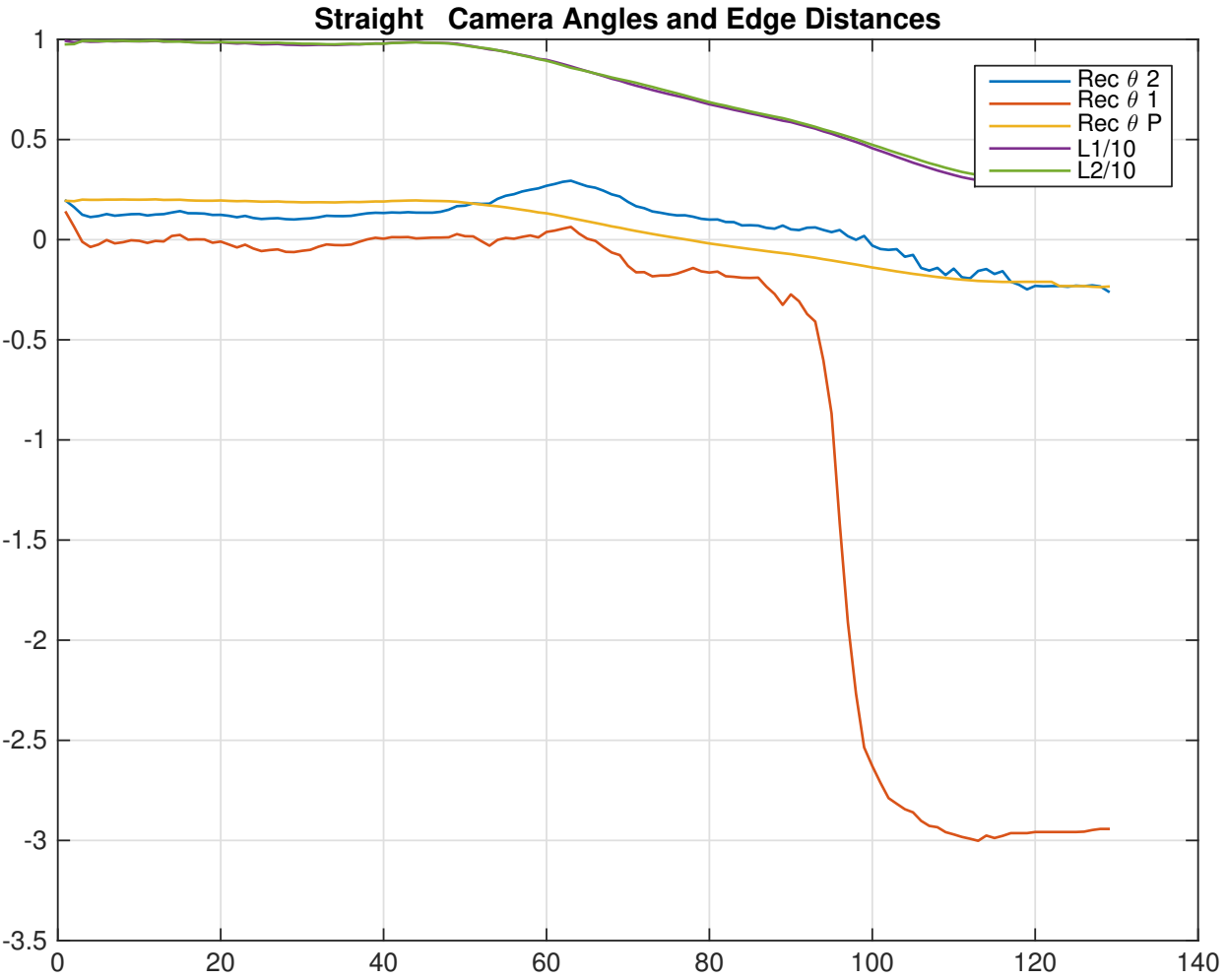

Straight Left_Edge vs Right_Edge
Left_Edge
Right_Edge
L1 x 100
L2 x 100
Distance (m) & Pixel
Index
1000
900
800
700
600
500
400
300
200
0
20
40
60
80
100
120
140

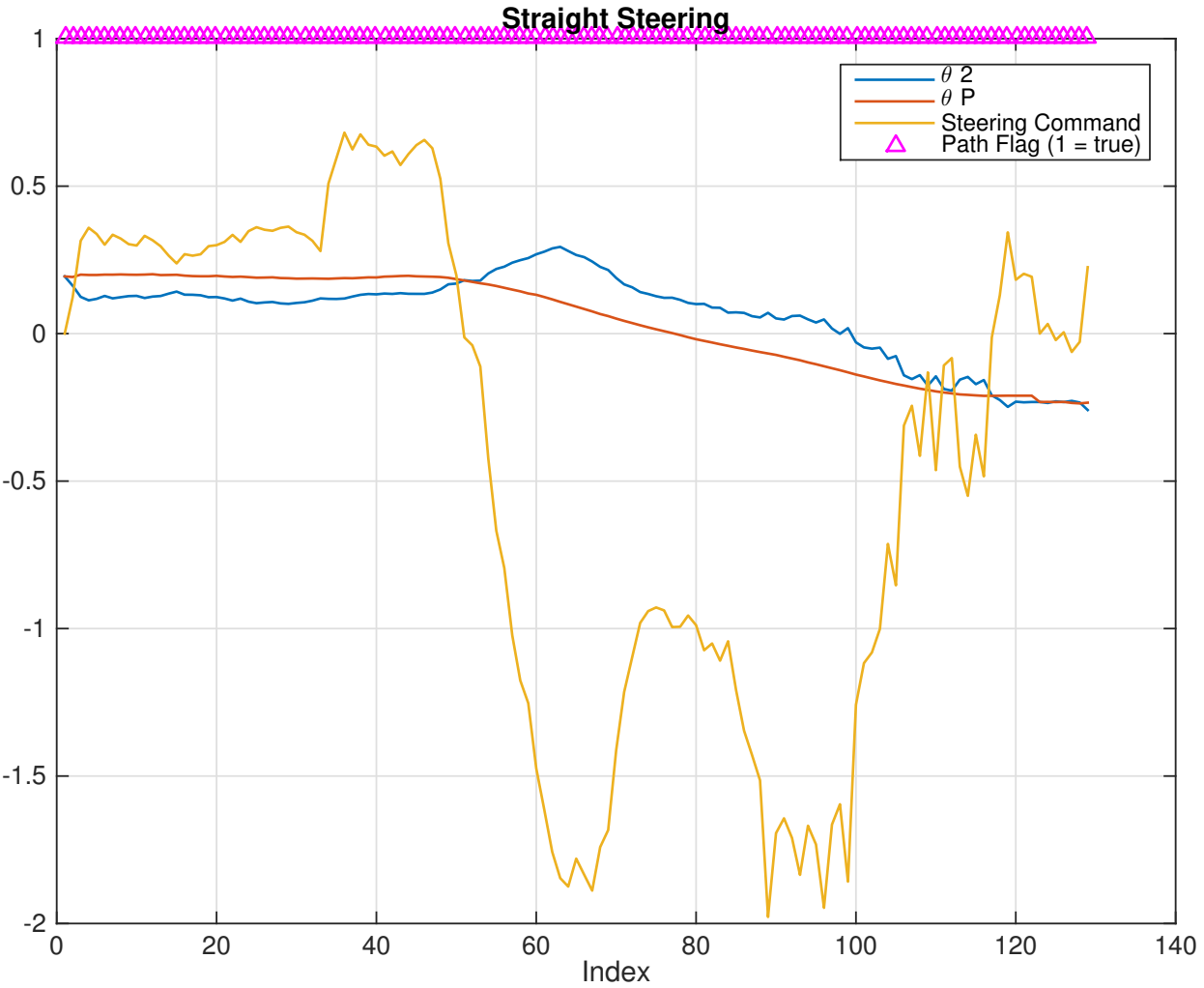

Straight LIDAR Distance vs Camera Center Distance
Upper LIDAR Distance
Center_Dist
Distance (m)
Index
0
2
4
6
8
10
12
14
16
0
20
40
60
80
100
120
140


Straight Camera L1 vs L2
L1
L2
Distance (m)
Index
10
9
8
7
6
5
4
3
2
0
20
40
60
80
100
120
140


Straight Camera Theta_1 vs Theta_2
θ 1
θ 2
Angle (rad)
index
0.5
0
-0.5
-1
-1.5
-2
-2.5
-3
-3.5
0
20
40
60
80
100
120
140


Straight LIDAR Theta_1 vs Theta_2
θ 1
θ 2
Angle (rad)
Index
4
3
2
1
0
-1
-2
-3
-4
0
20
40
60
80
100
120
140


Straight Camera Angles and Edge Distances
Rec θ 2
Rec θ 1
Rec θ P
L1/10
L2/10
1
0.5
0
-0.5
-1
-1.5
-2
-2.5
-3
-3.5
0
20
40
60
80
100
120
140


Straight Steering
θ 2
θ P
Steering Command
Path Flag (1 = true)
1
0.5
0
-0.5
-1
-1.5
-2
0
20
40
60
80
100
120
140
Index