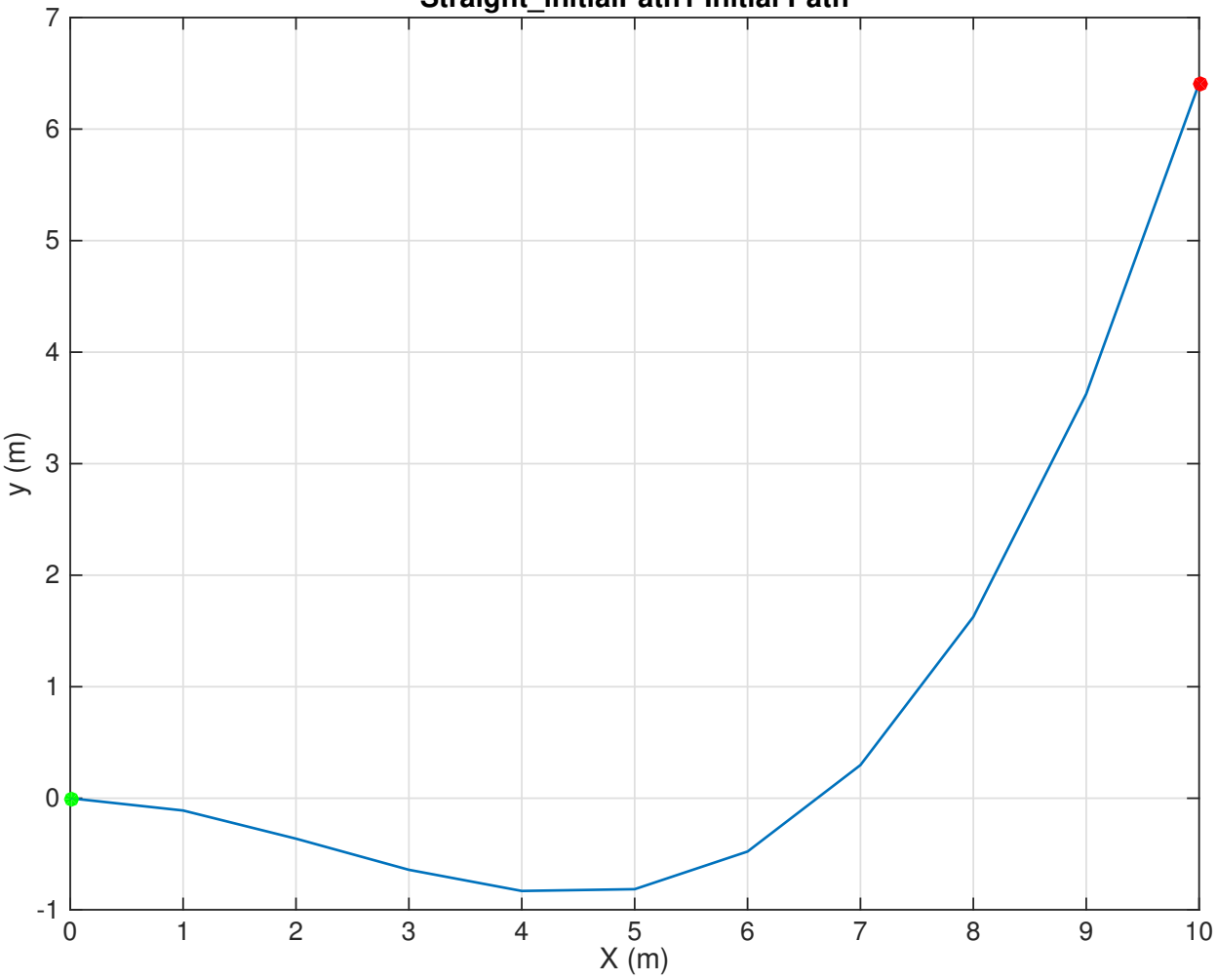


Straight\_initialPath1 Initial Path



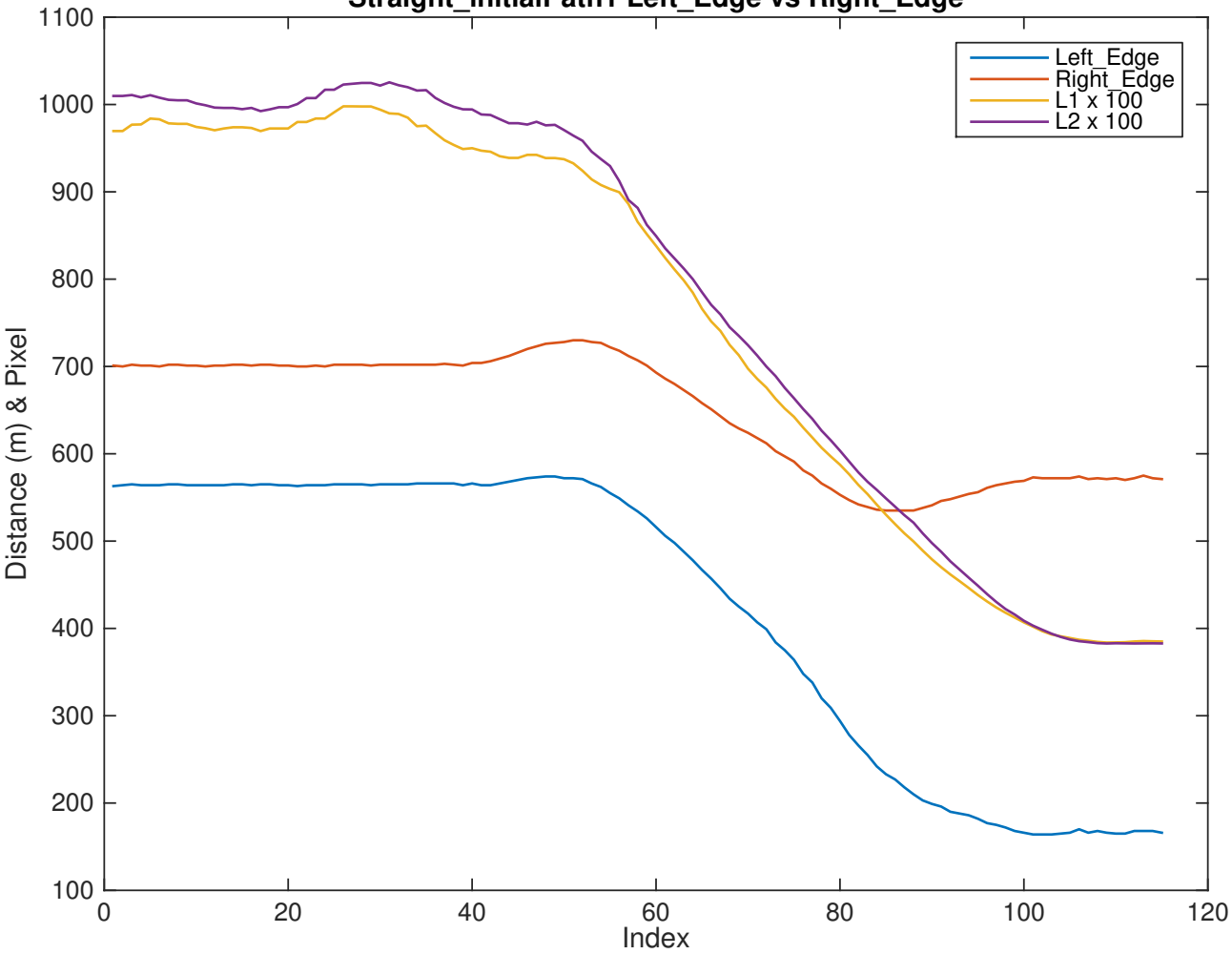
Number\_Of\_Unique\_Paths

King\_Pin\_Detected

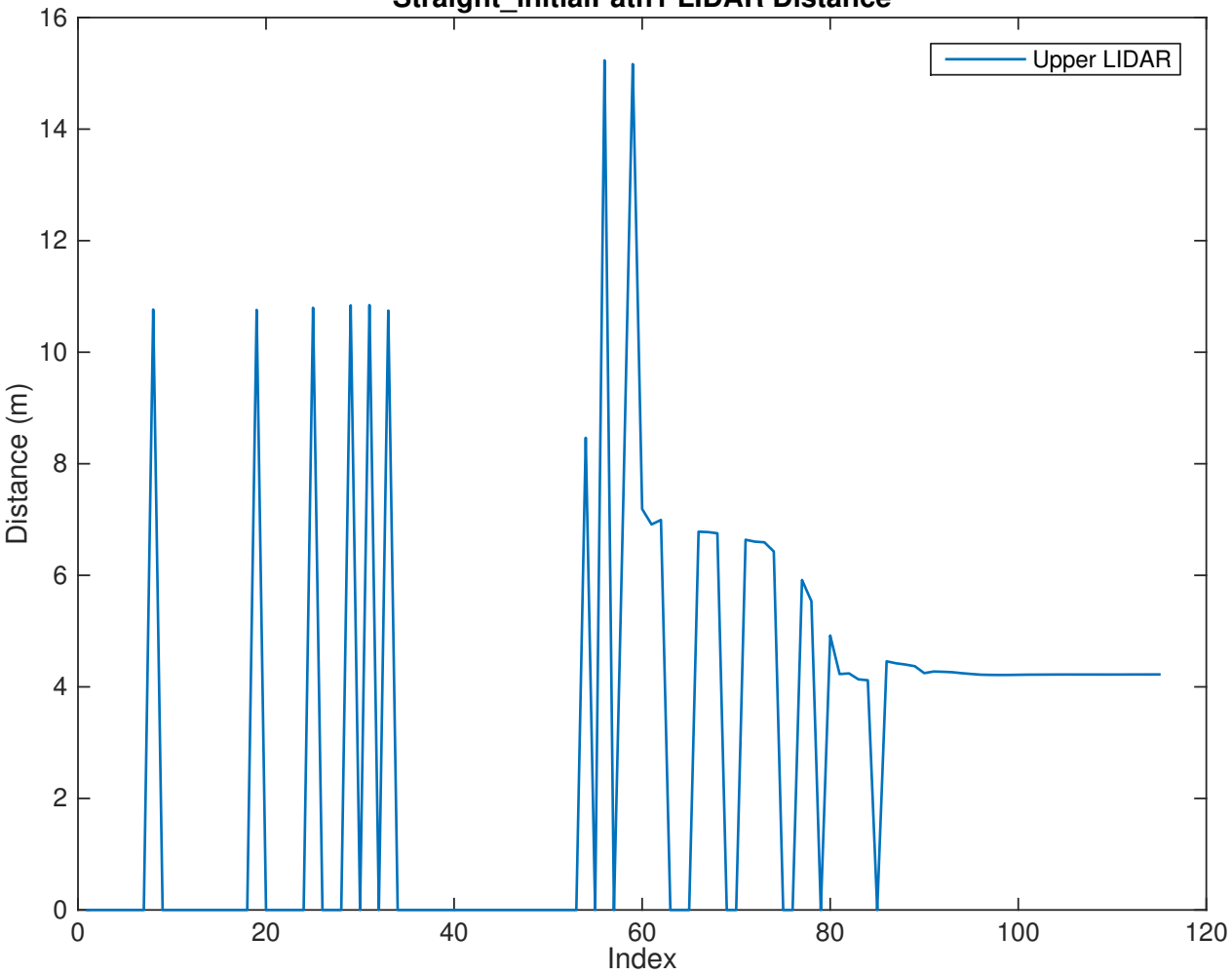
2

false

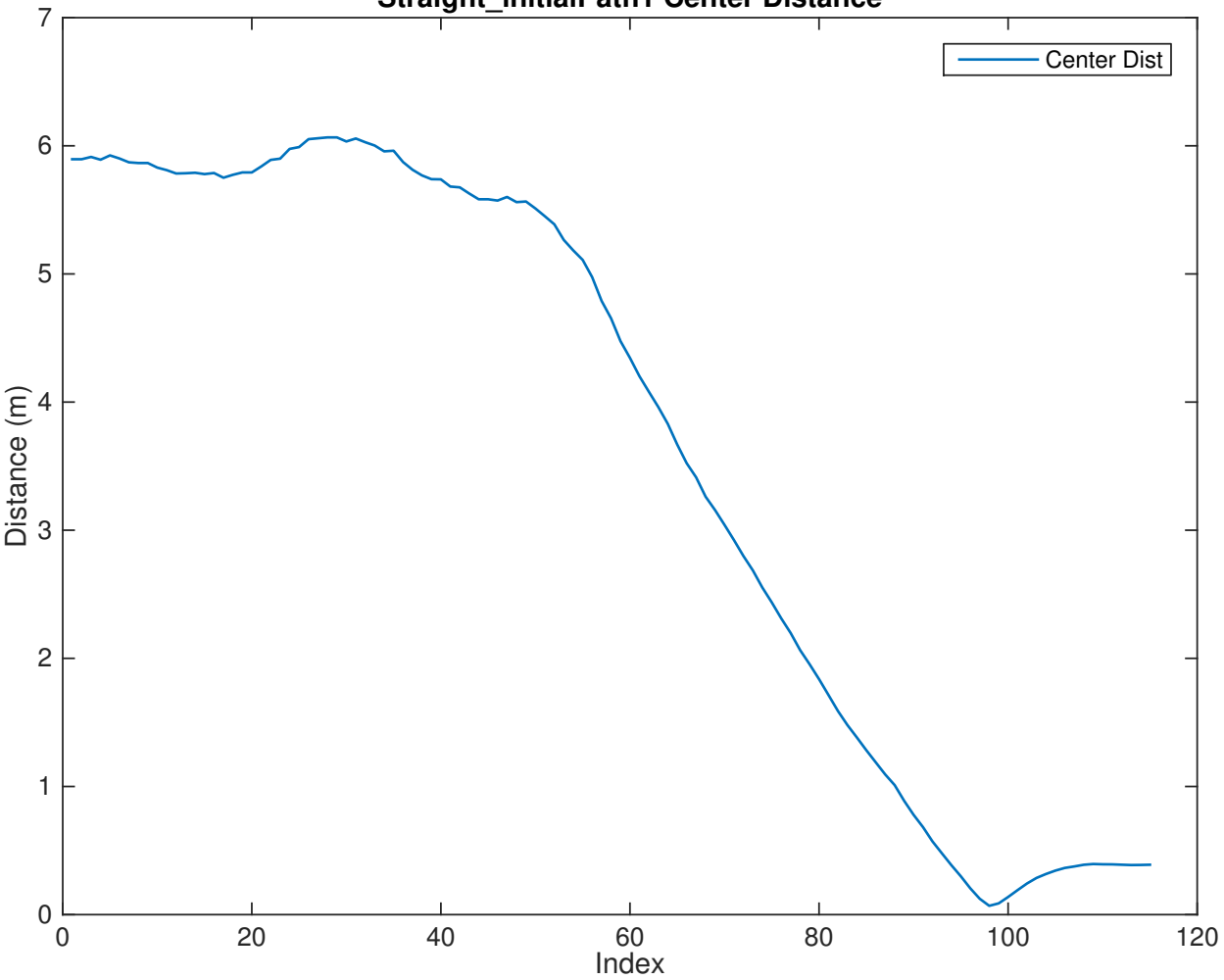
Straight\_initialPath1 Left\_Edge vs Right\_Edge



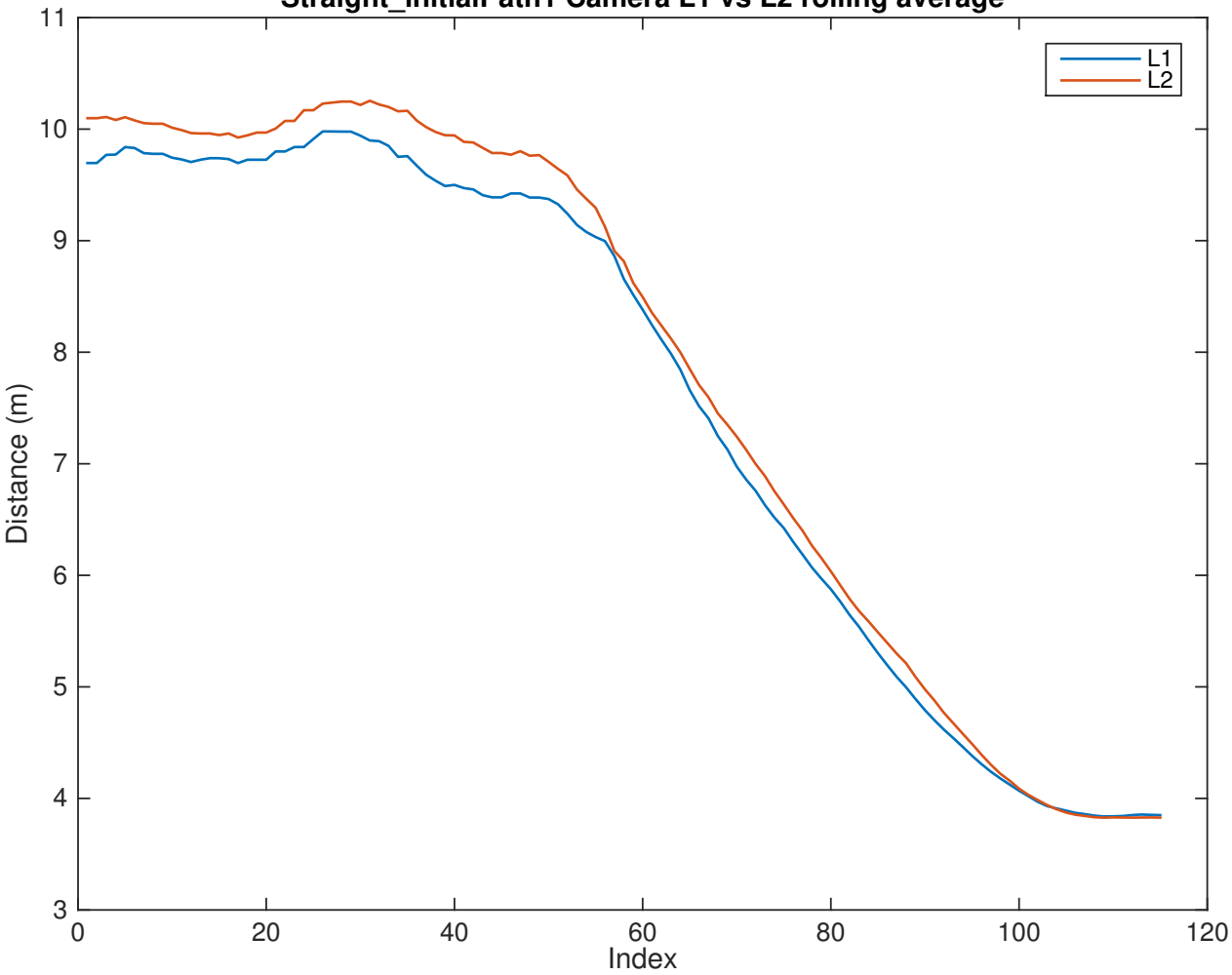
Straight\_initialPath1 LIDAR Distance



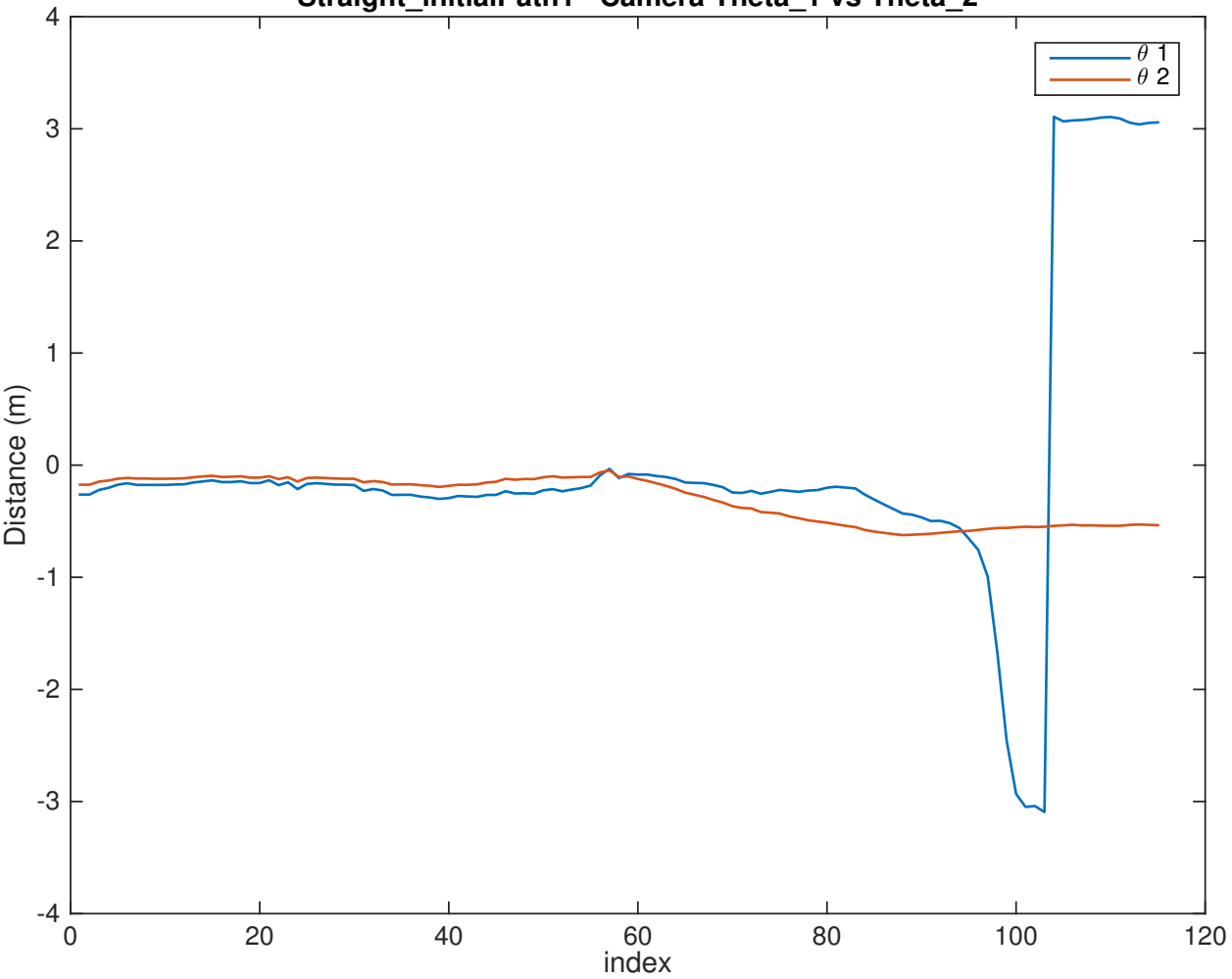
Straight\_initialPath1 Center Distance



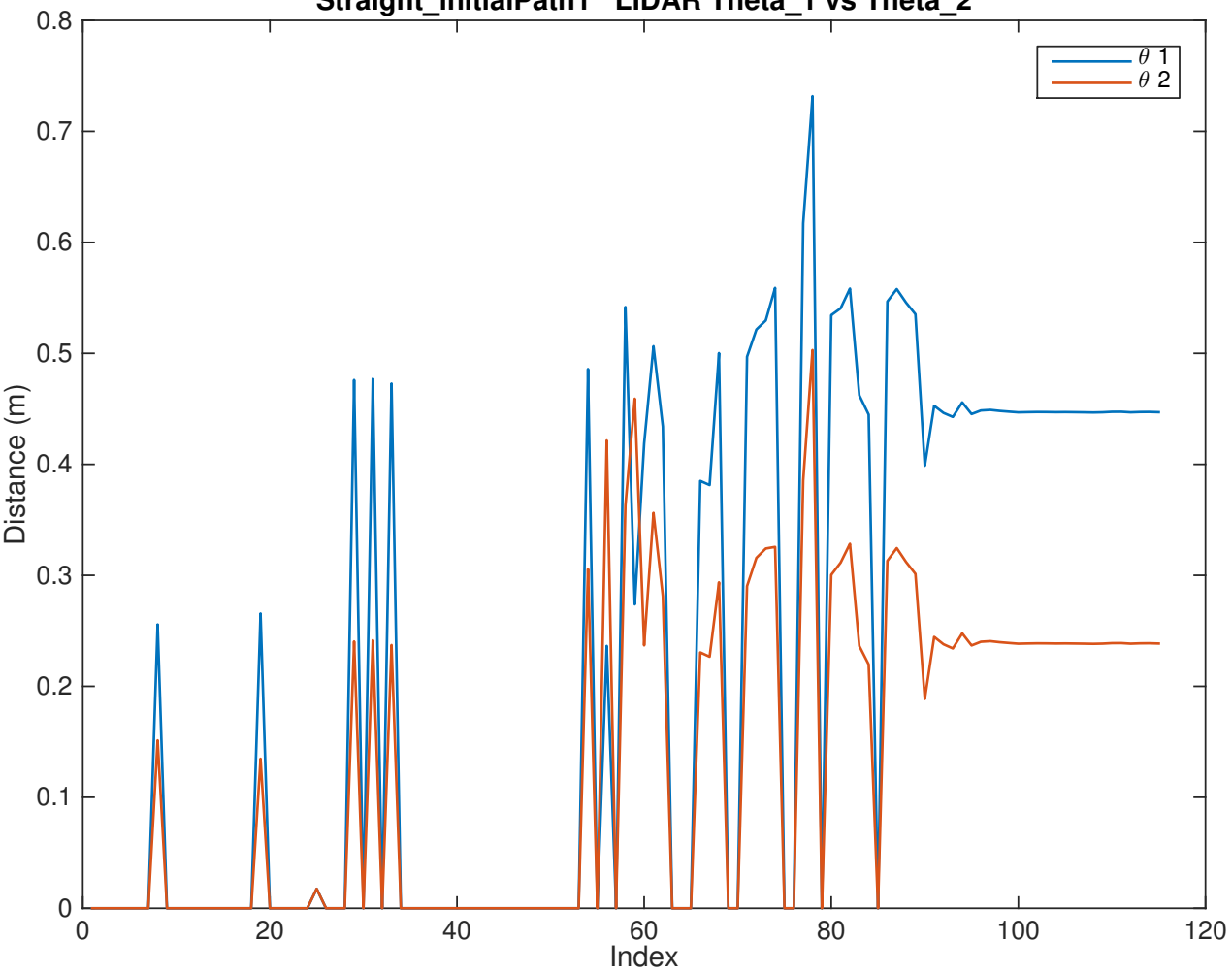
Straight\_initialPath1 Camera L1 vs L2 rolling average



Straight\_initialPath1 Camera Theta\_1 vs Theta\_2

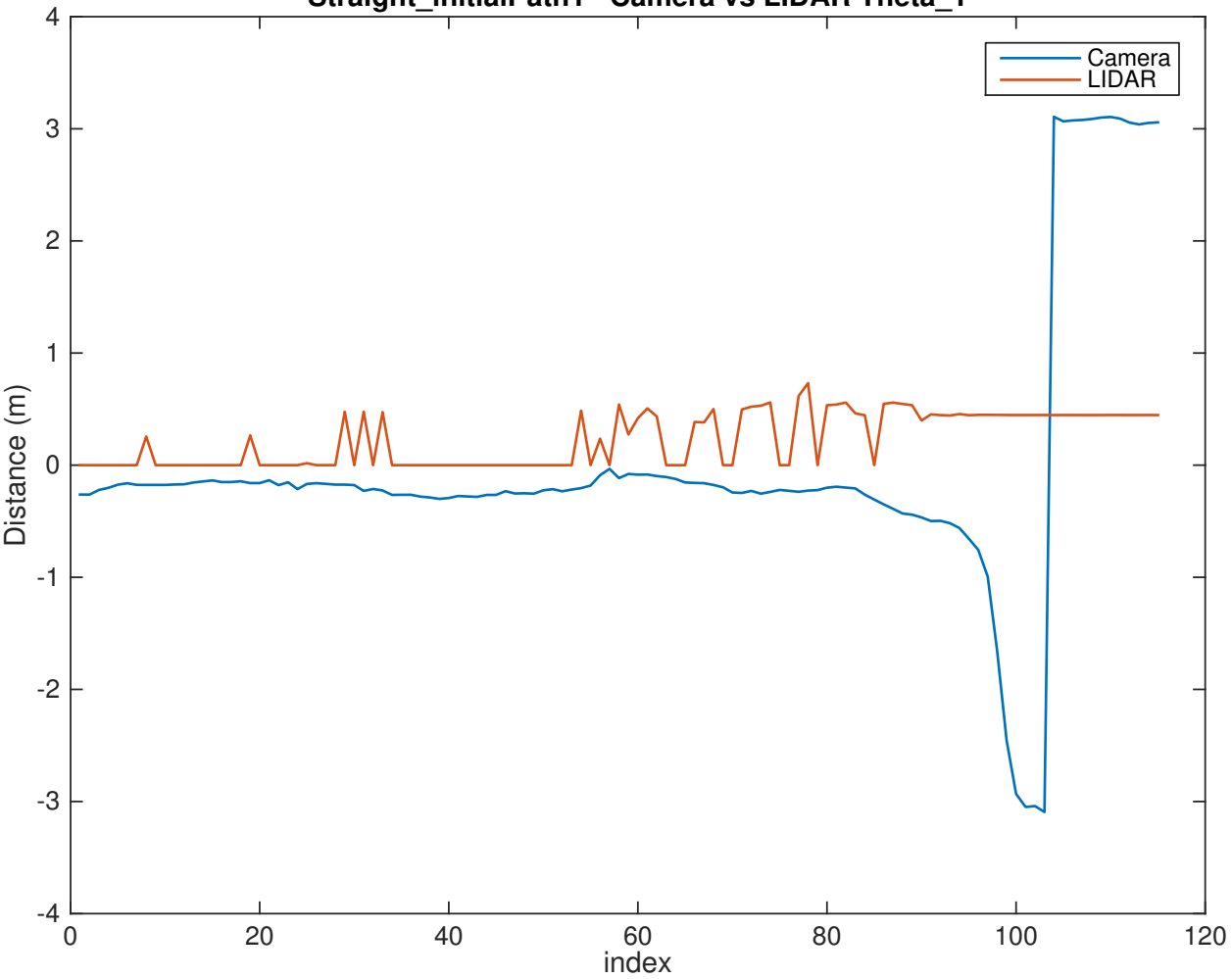


Straight\_initialPath1 LIDAR Theta\_1 vs Theta\_2

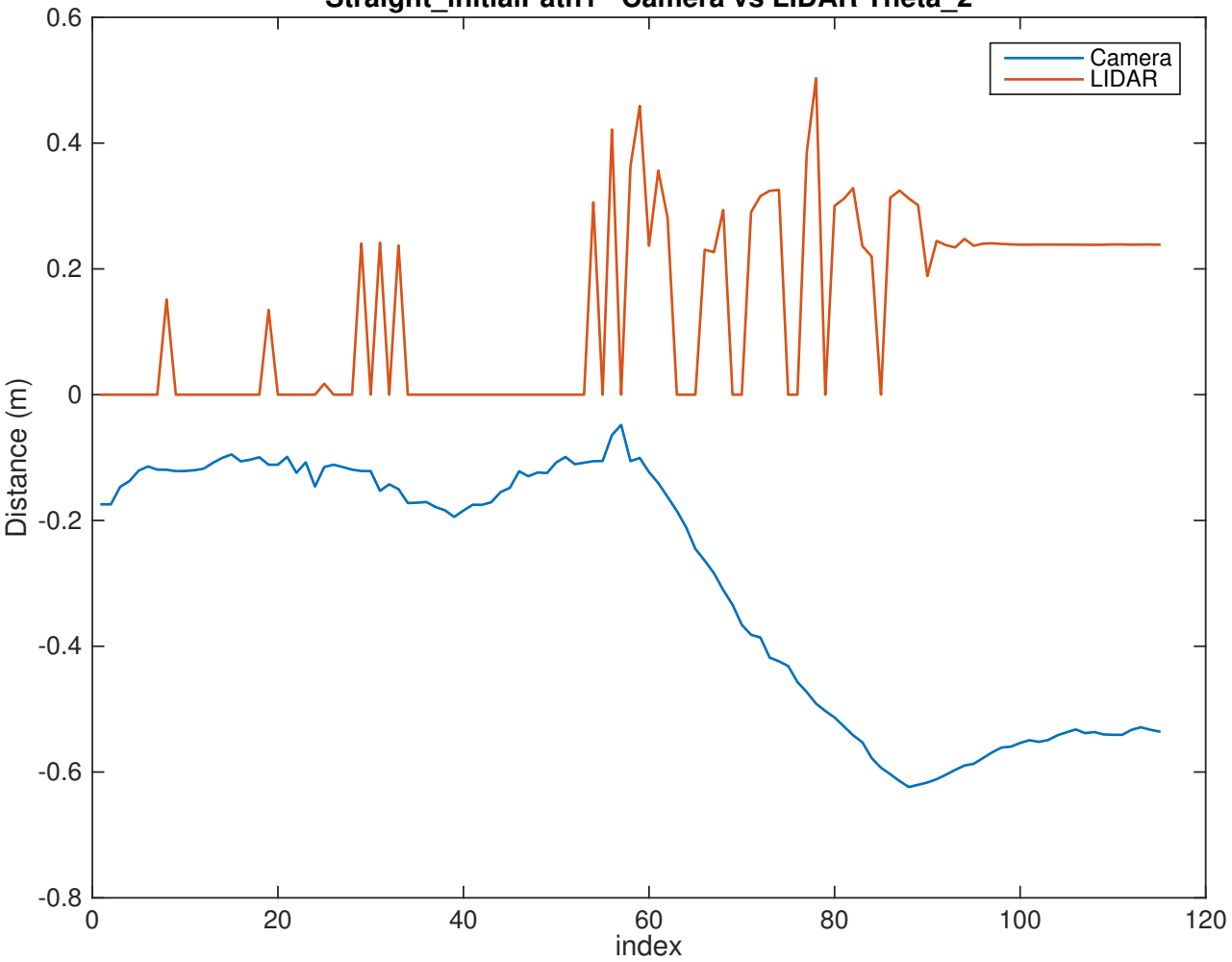




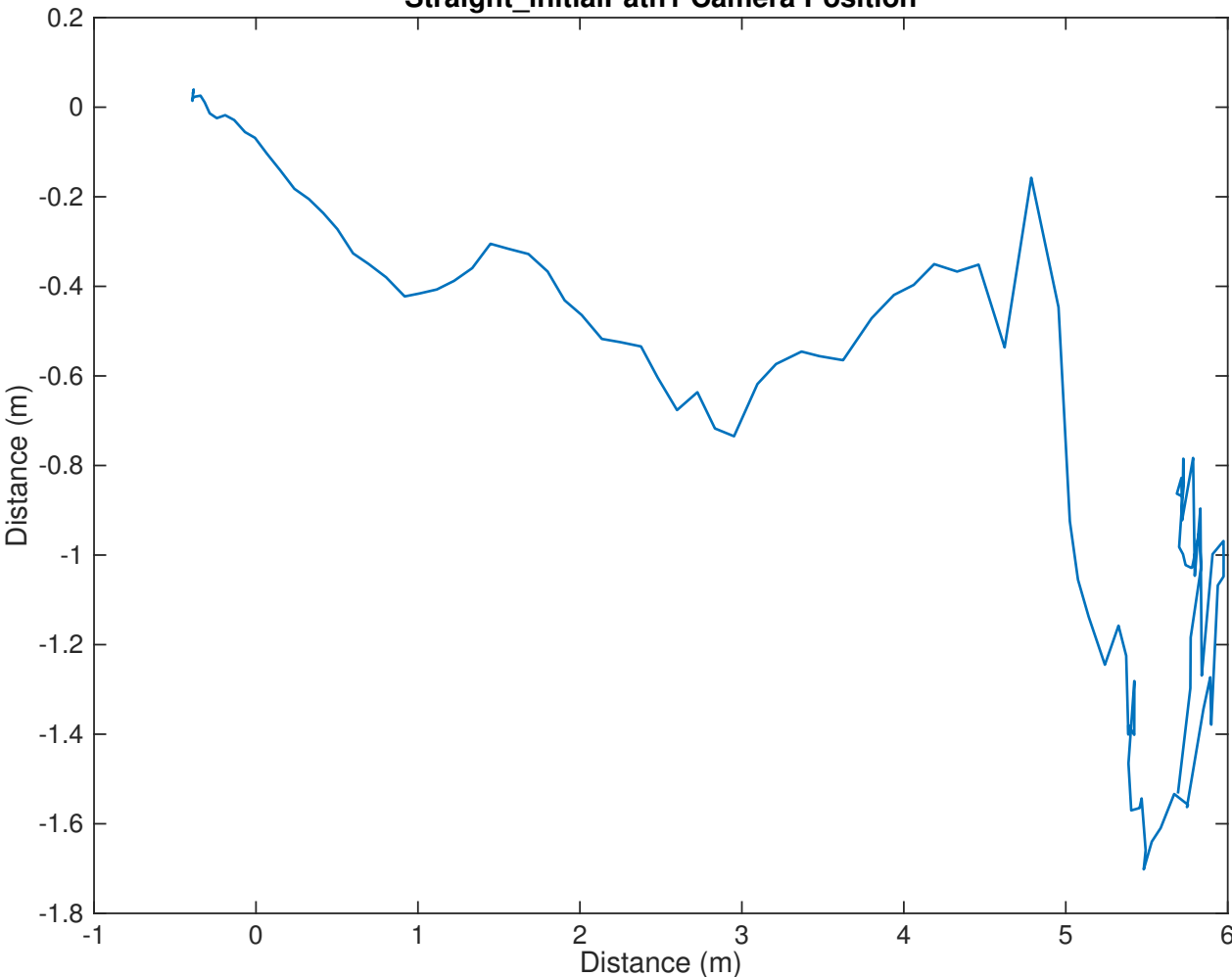
Straight\_initialPath1 Camera vs LIDAR Theta\_1



Straight\_initialPath1 Camera vs LIDAR Theta\_2

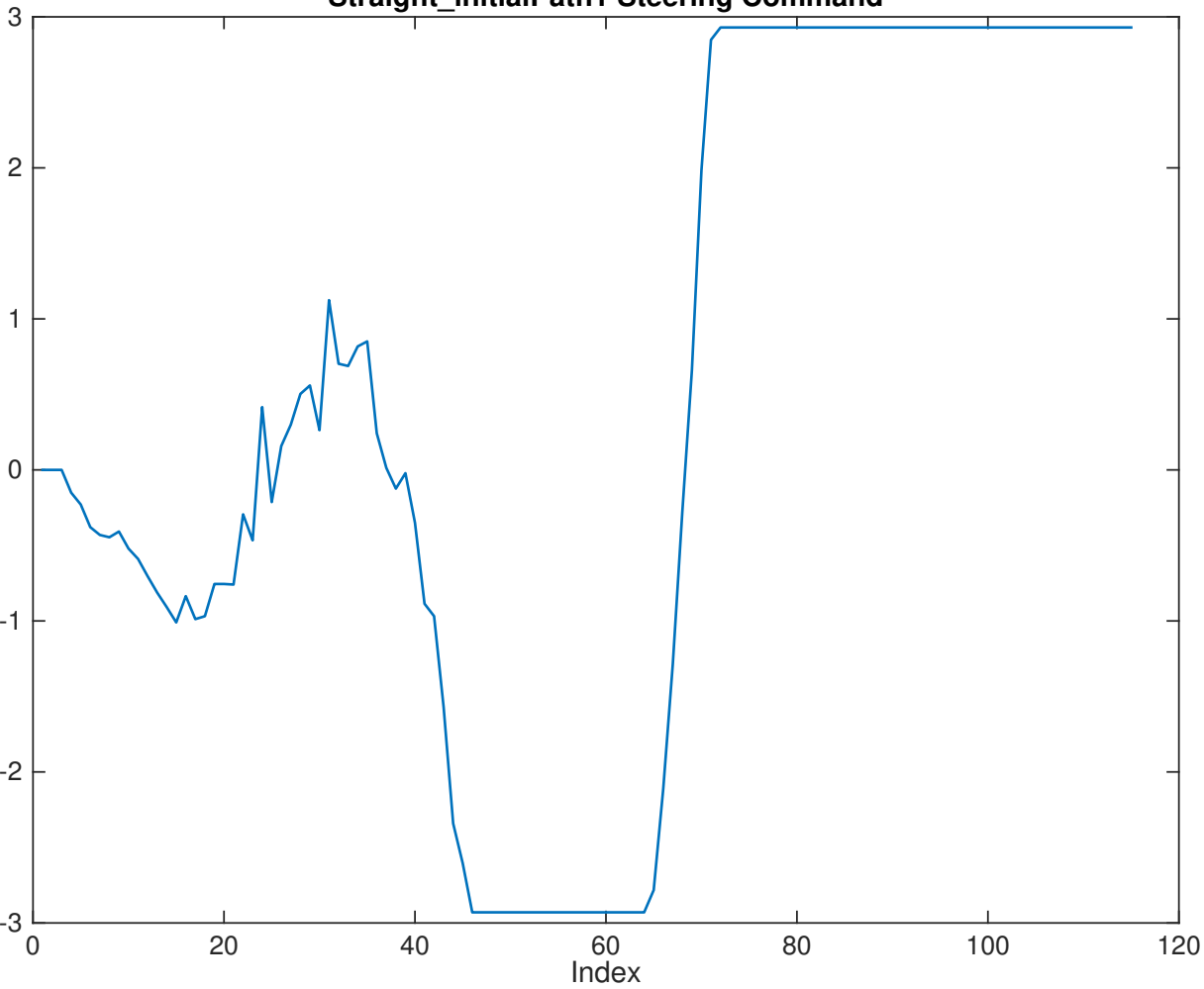


Straight\_initialPath1 Camera Position

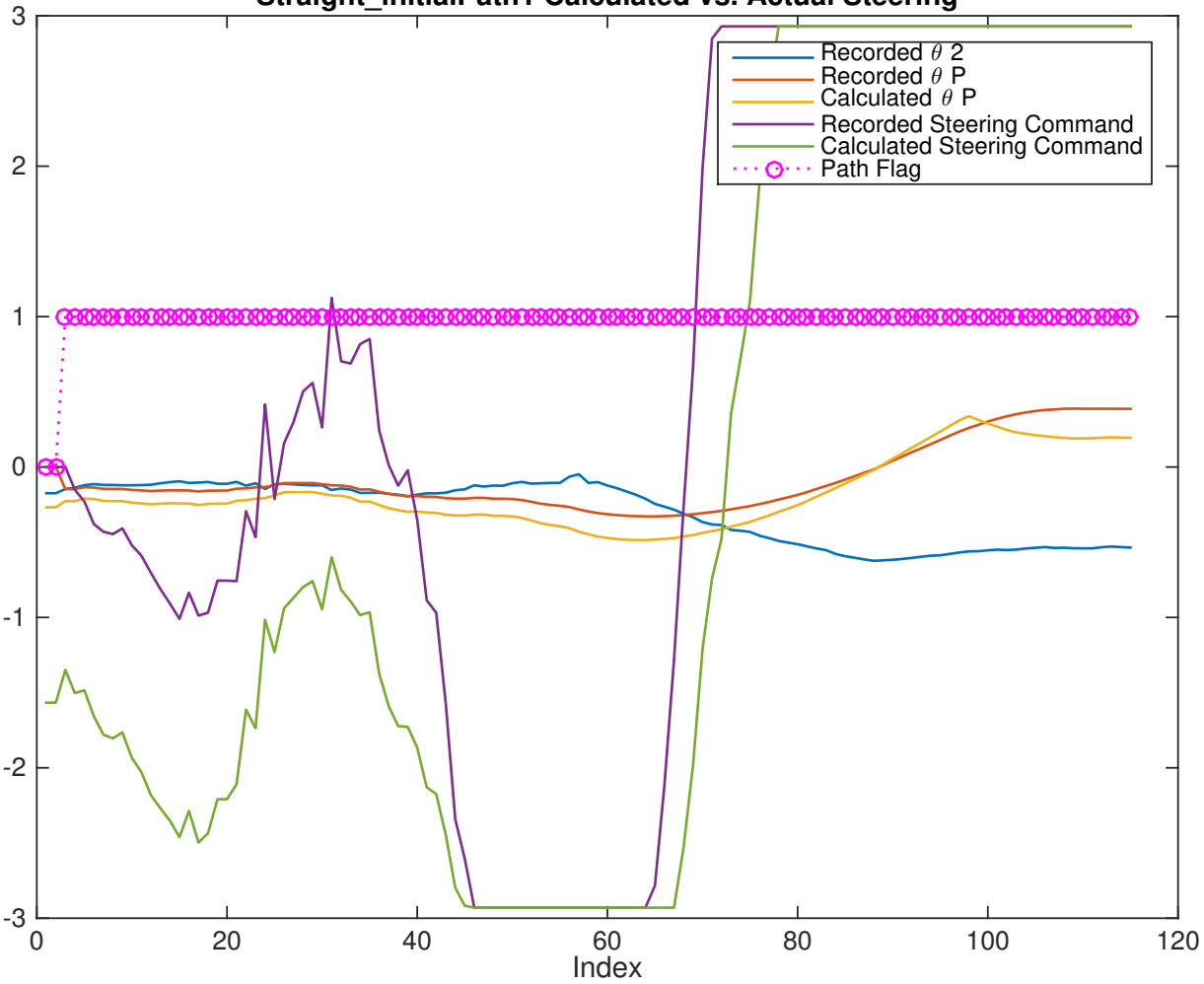


Straight\_initialPath1 Steering Command

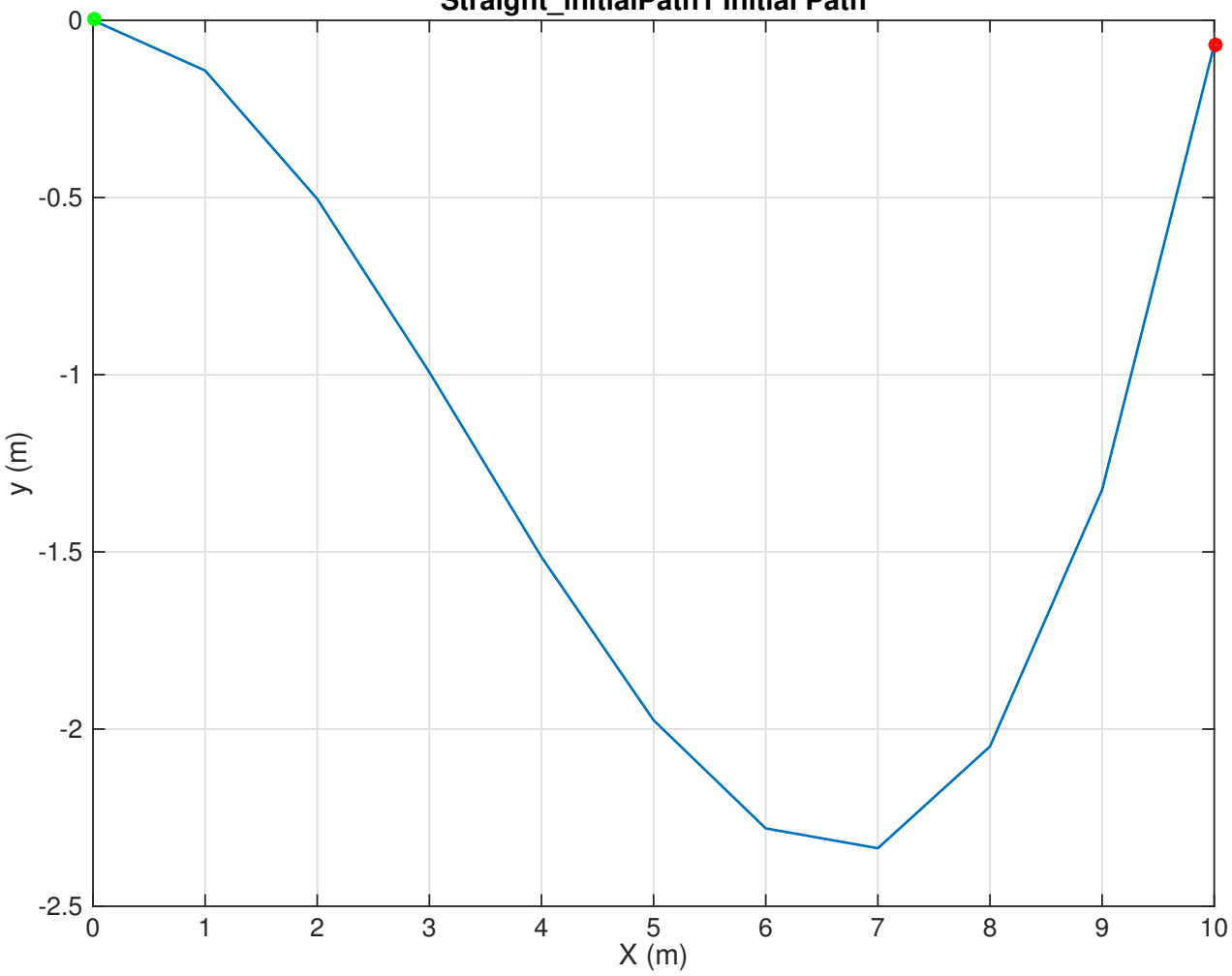
Turns (Clockwise Positive) 1 = 360° turn



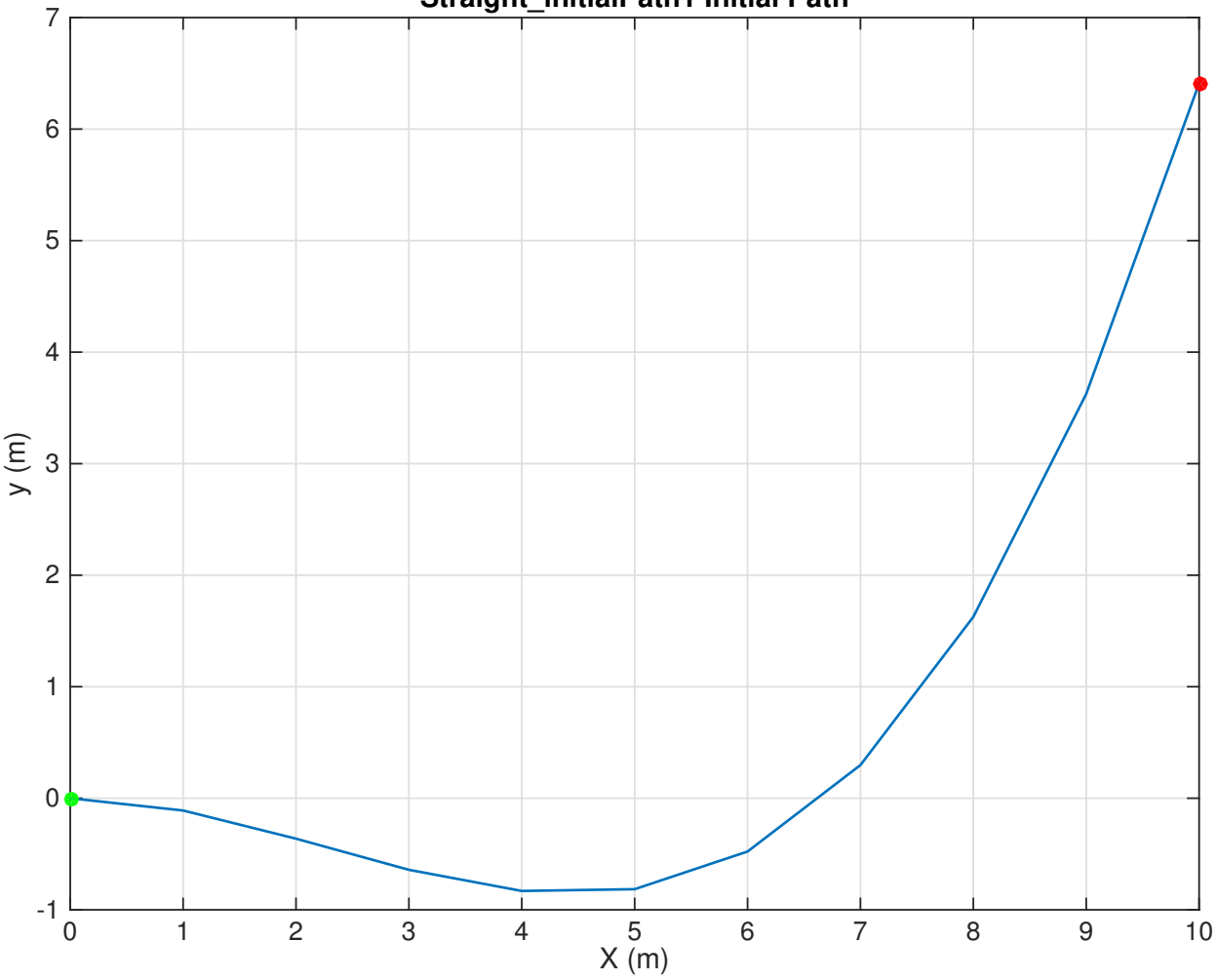
**Straight\_initialPath1 Calculated vs. Actual Steering**



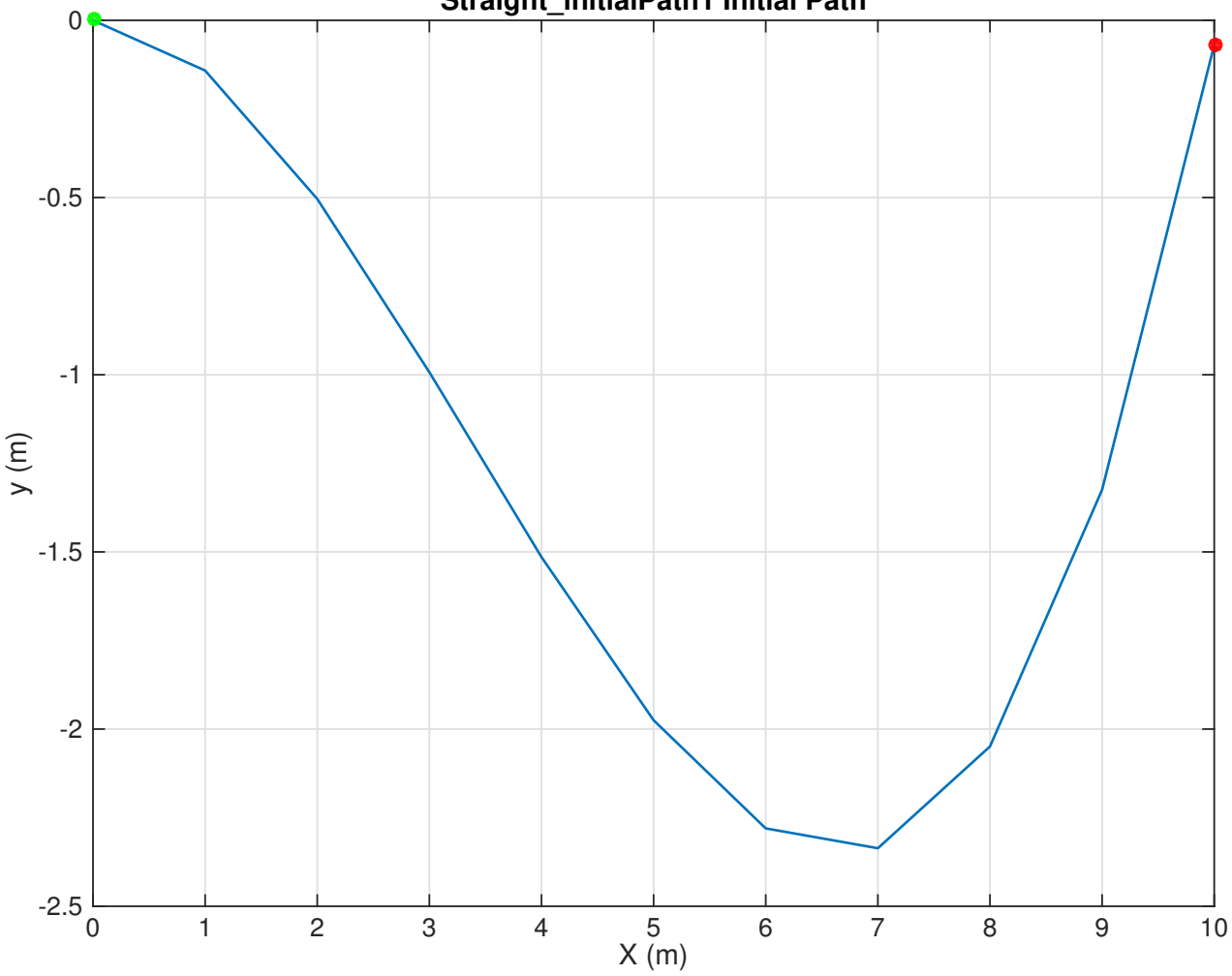
Straight\_initialPath1 Initial Path



Straight\_initialPath1 Initial Path

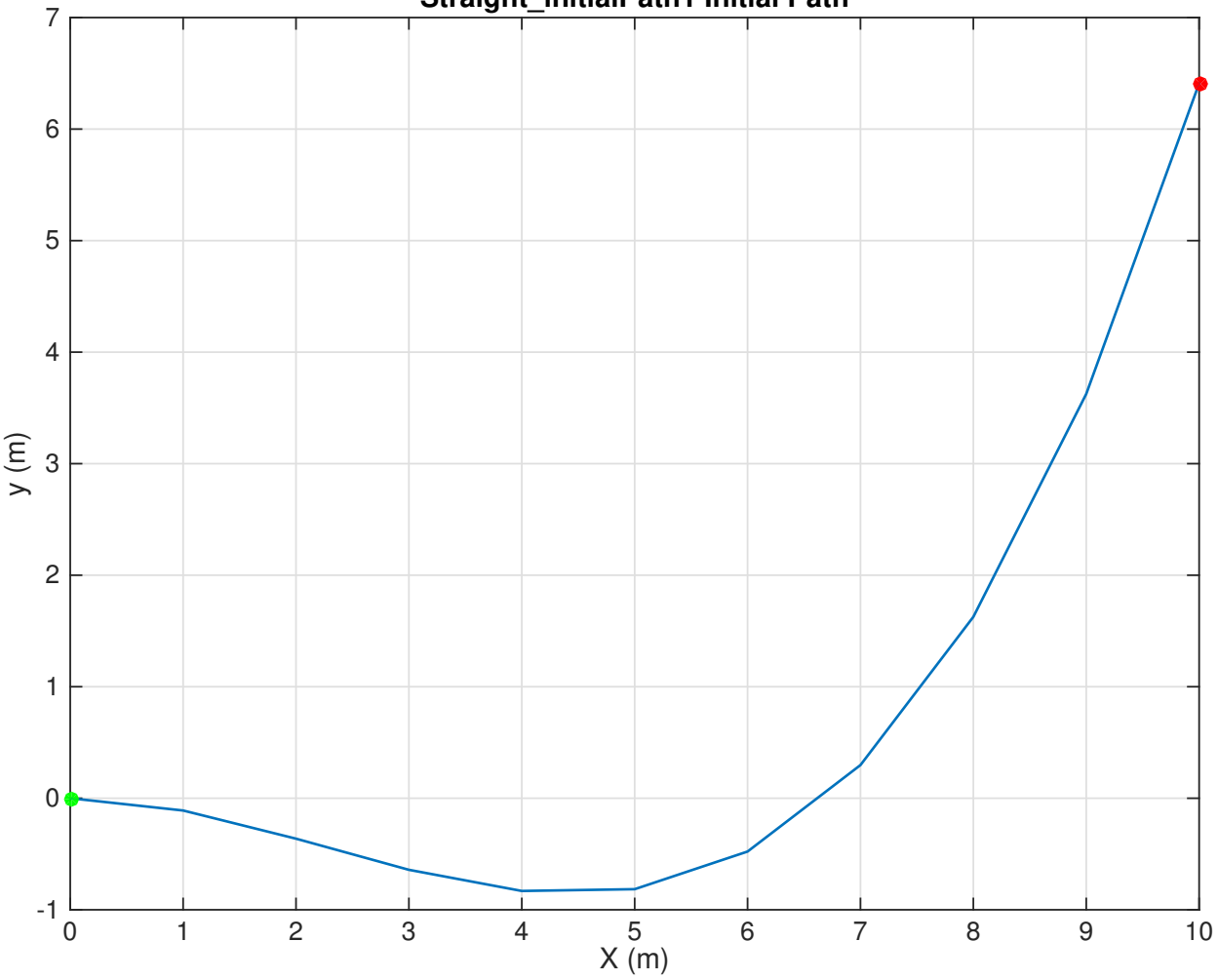


Straight\_initialPath1 Initial Path

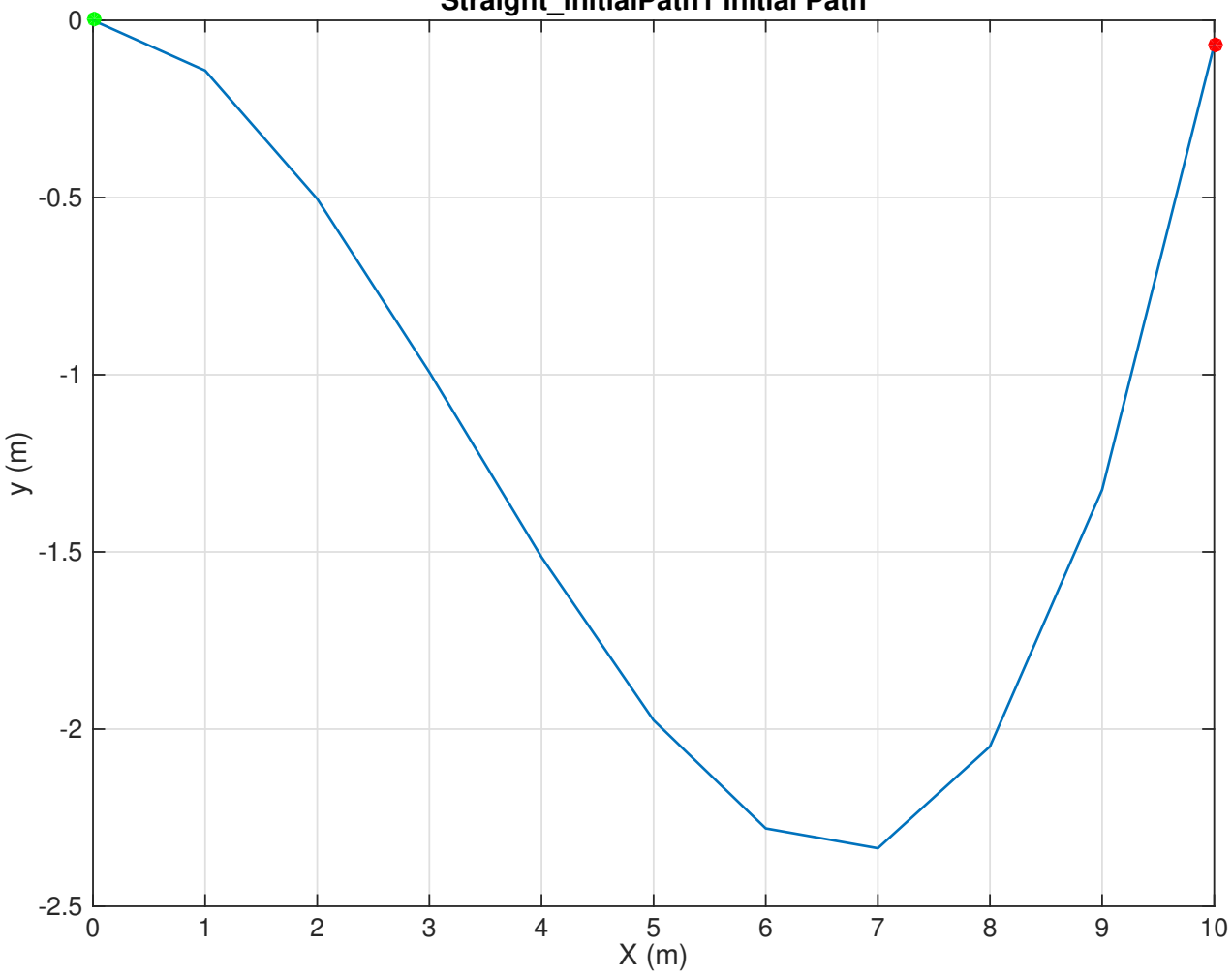




Straight\_initialPath1 Initial Path



Straight\_initialPath1 Initial Path



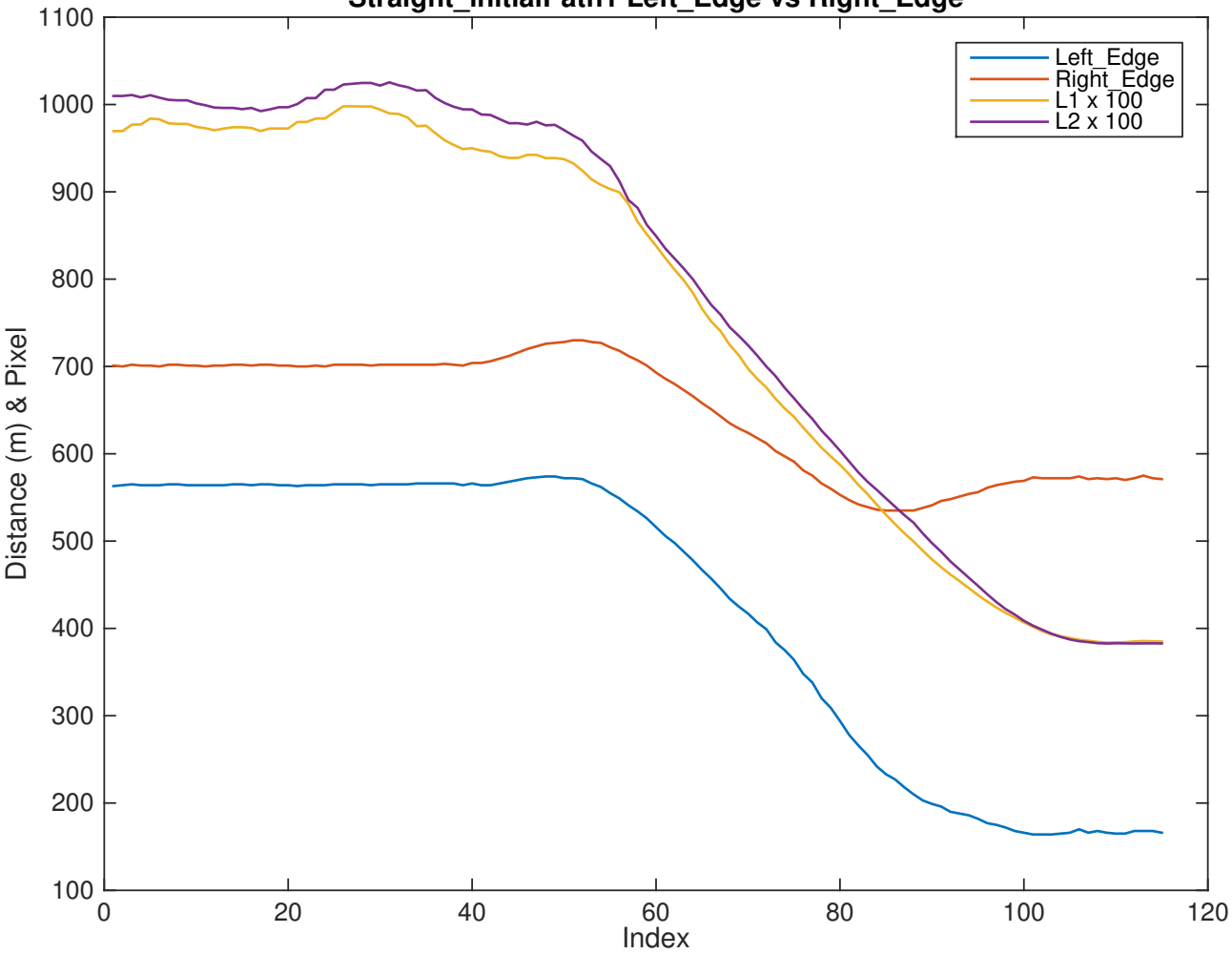
Number\_Of\_Unique\_Paths

King\_Pin\_Detected

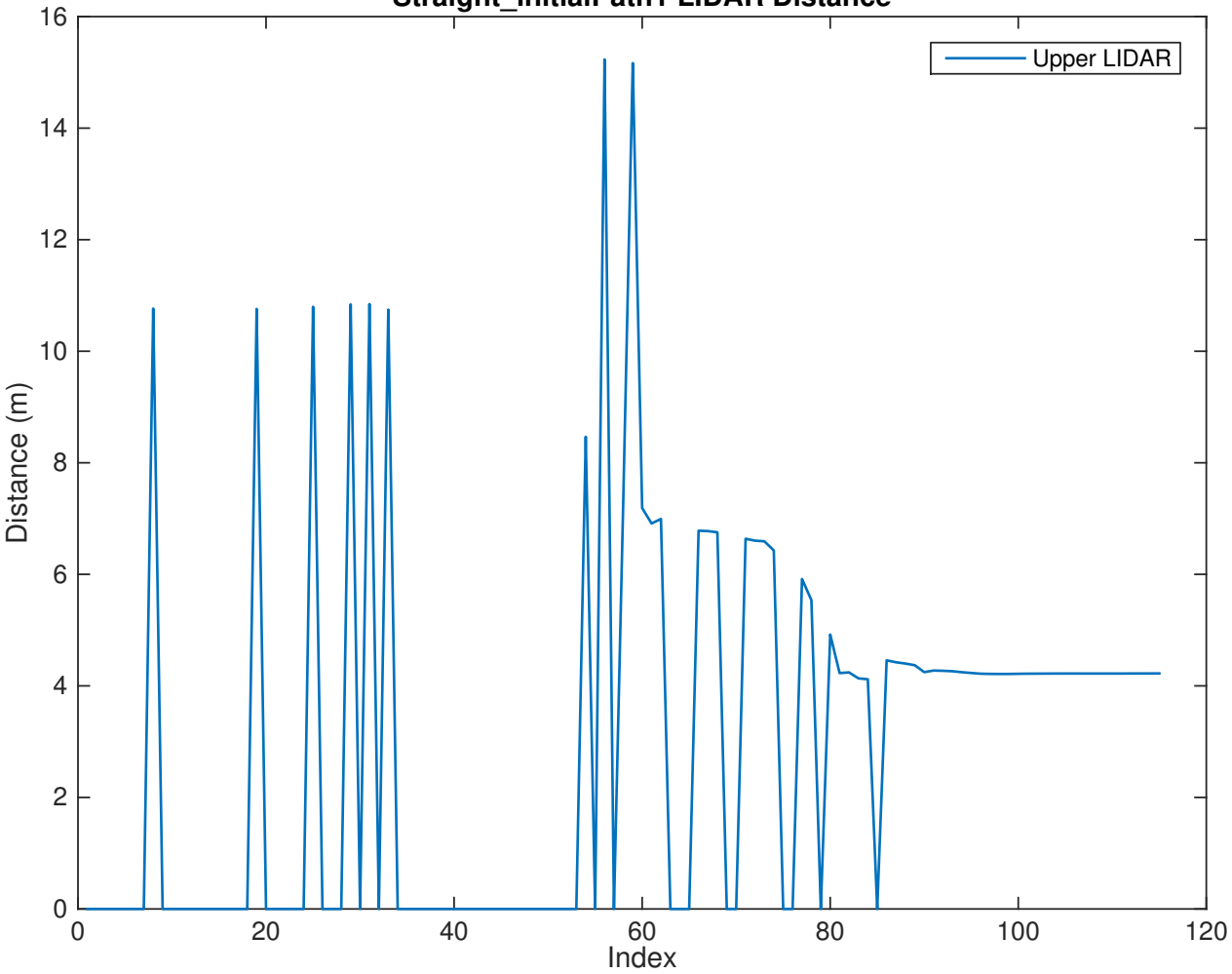
2

false

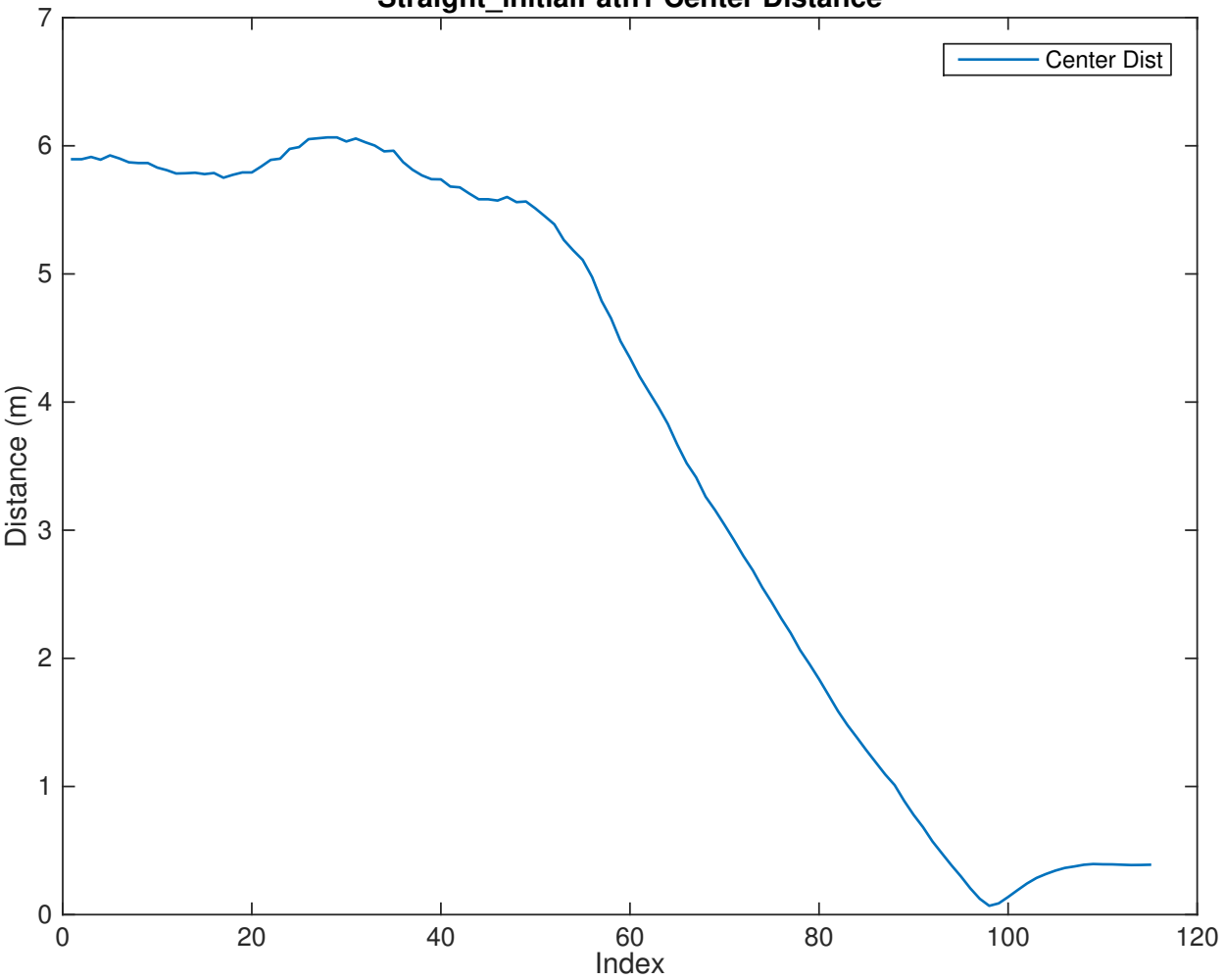
Straight\_initialPath1 Left\_Edge vs Right\_Edge



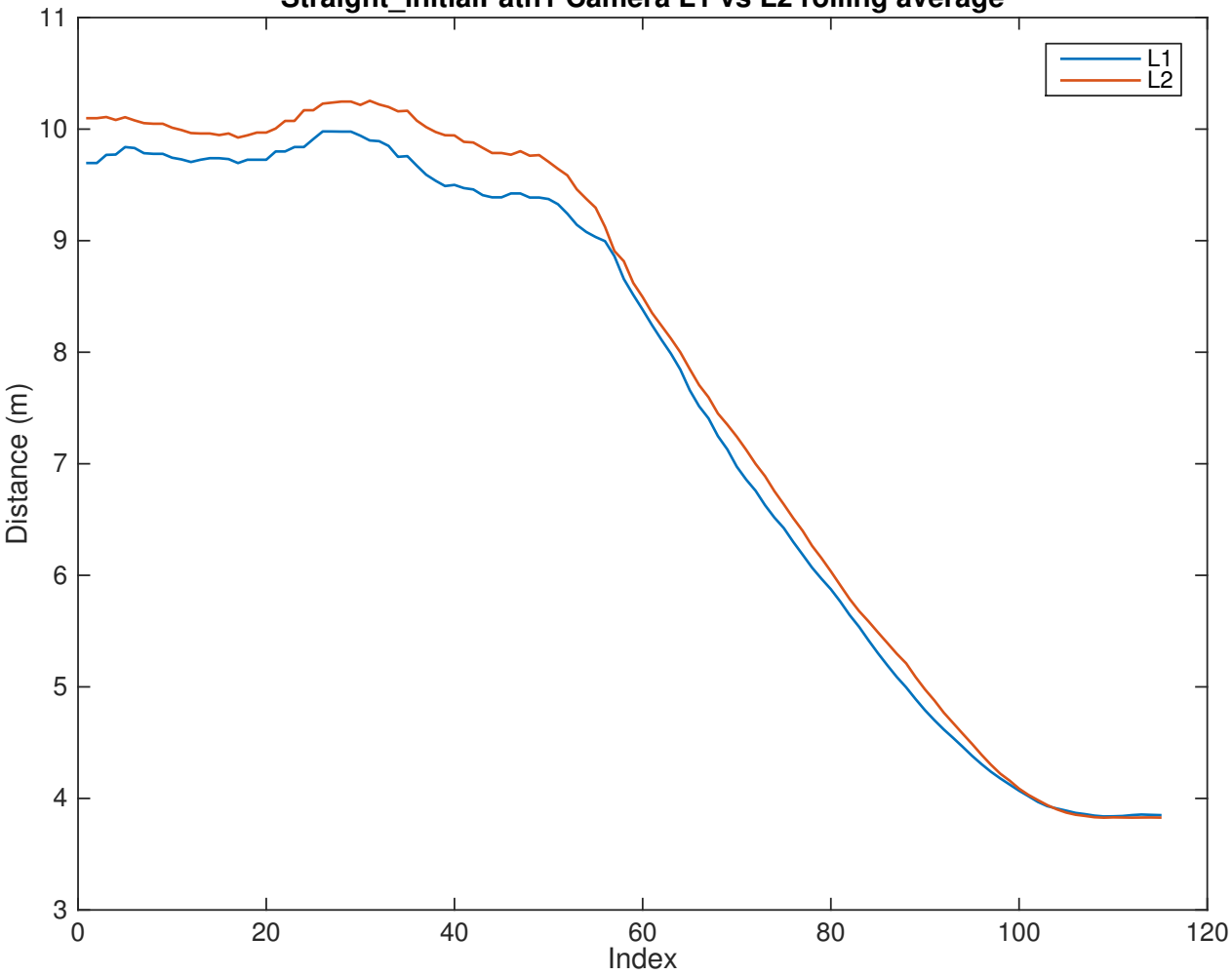
Straight\_initialPath1 LIDAR Distance



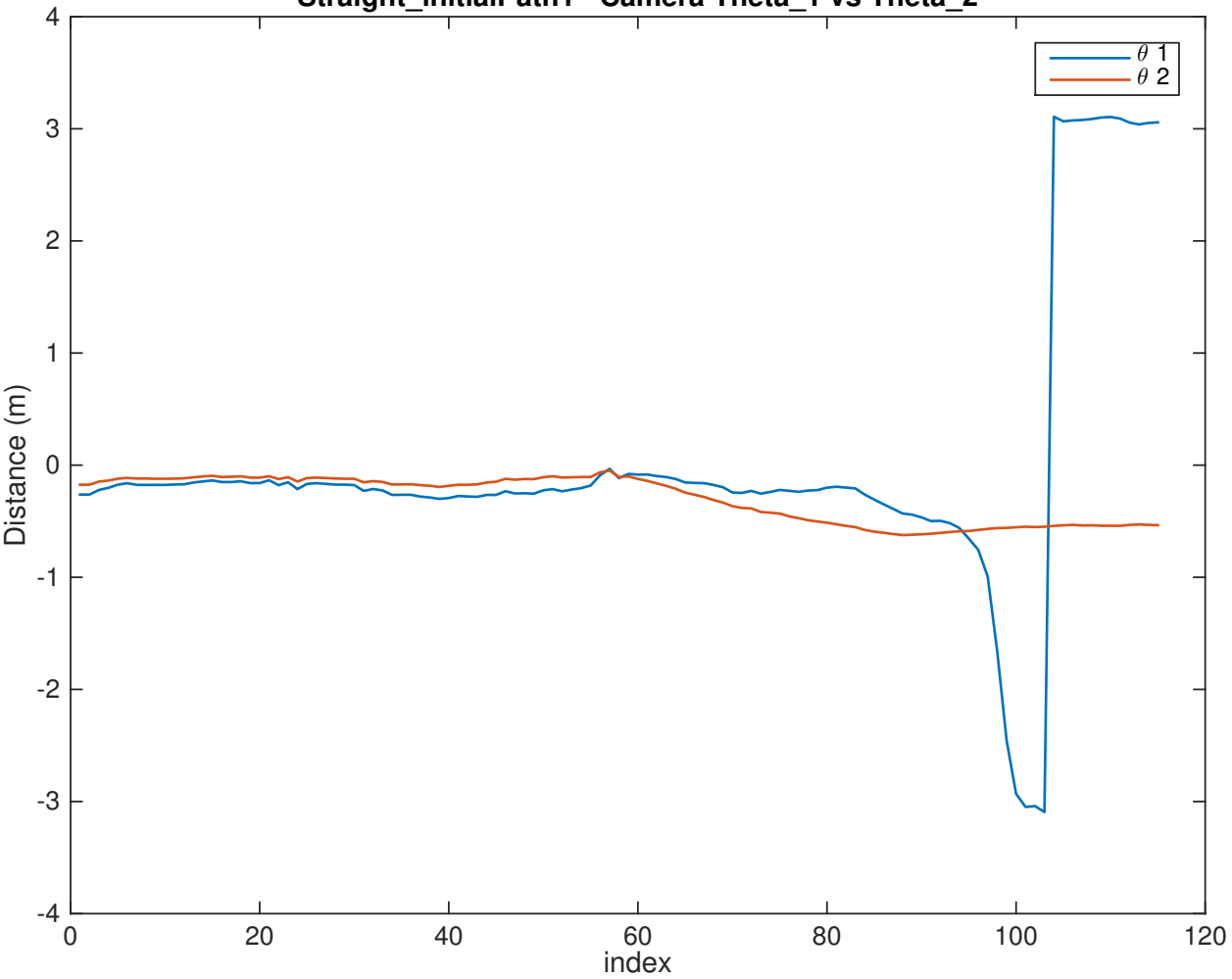
Straight\_initialPath1 Center Distance



Straight\_initialPath1 Camera L1 vs L2 rolling average

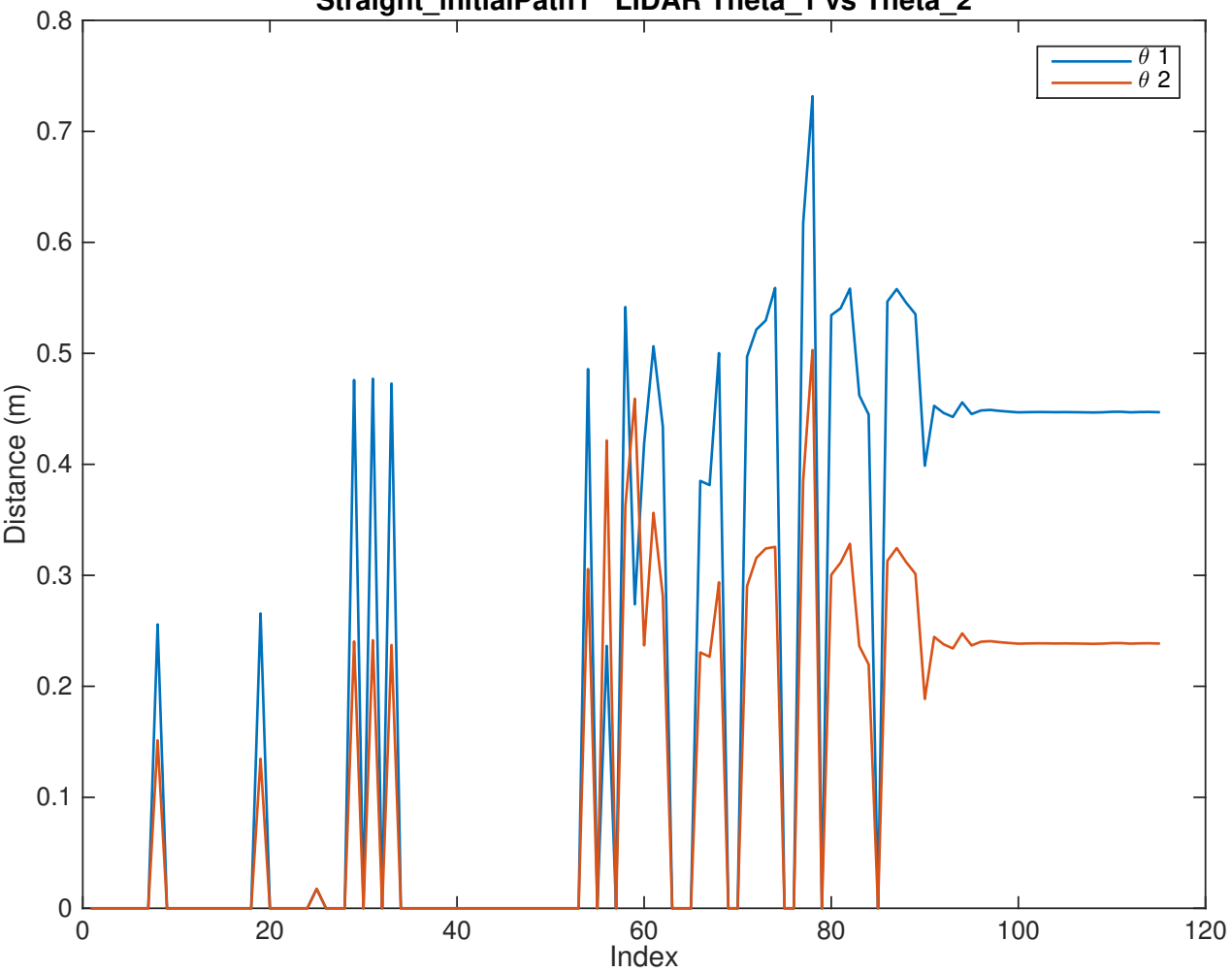


Straight\_initialPath1 Camera Theta\_1 vs Theta\_2

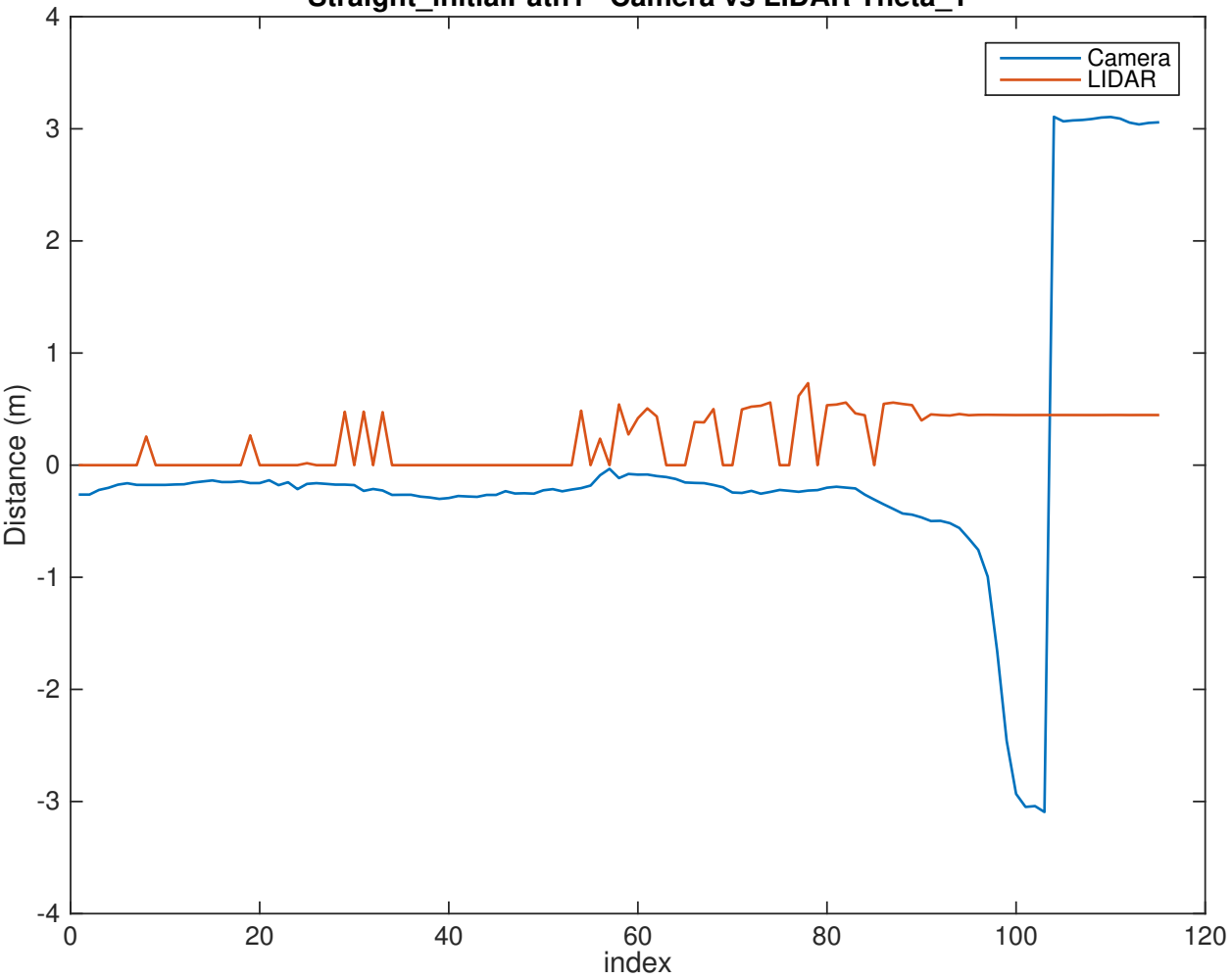




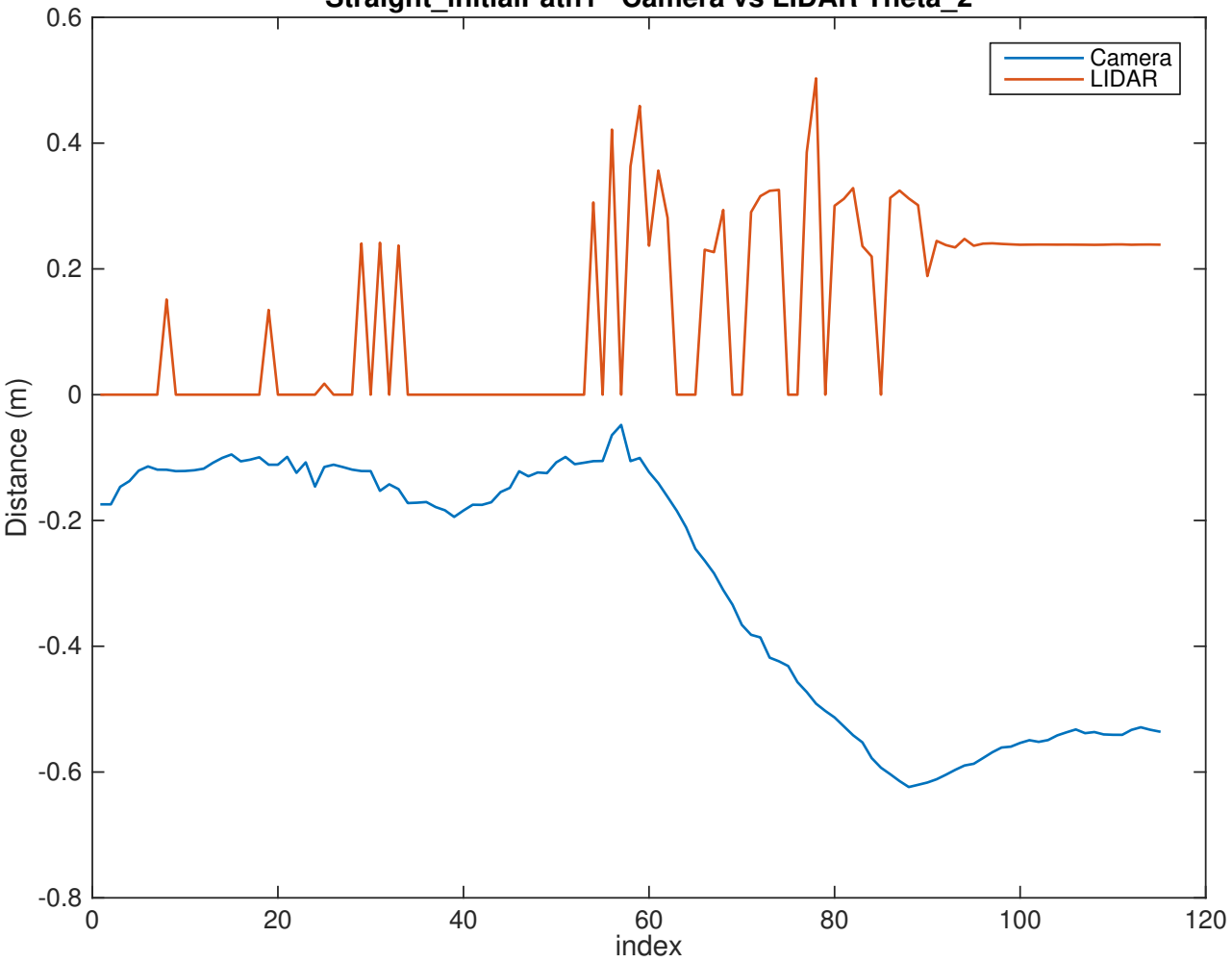
Straight\_initialPath1 LIDAR Theta\_1 vs Theta\_2



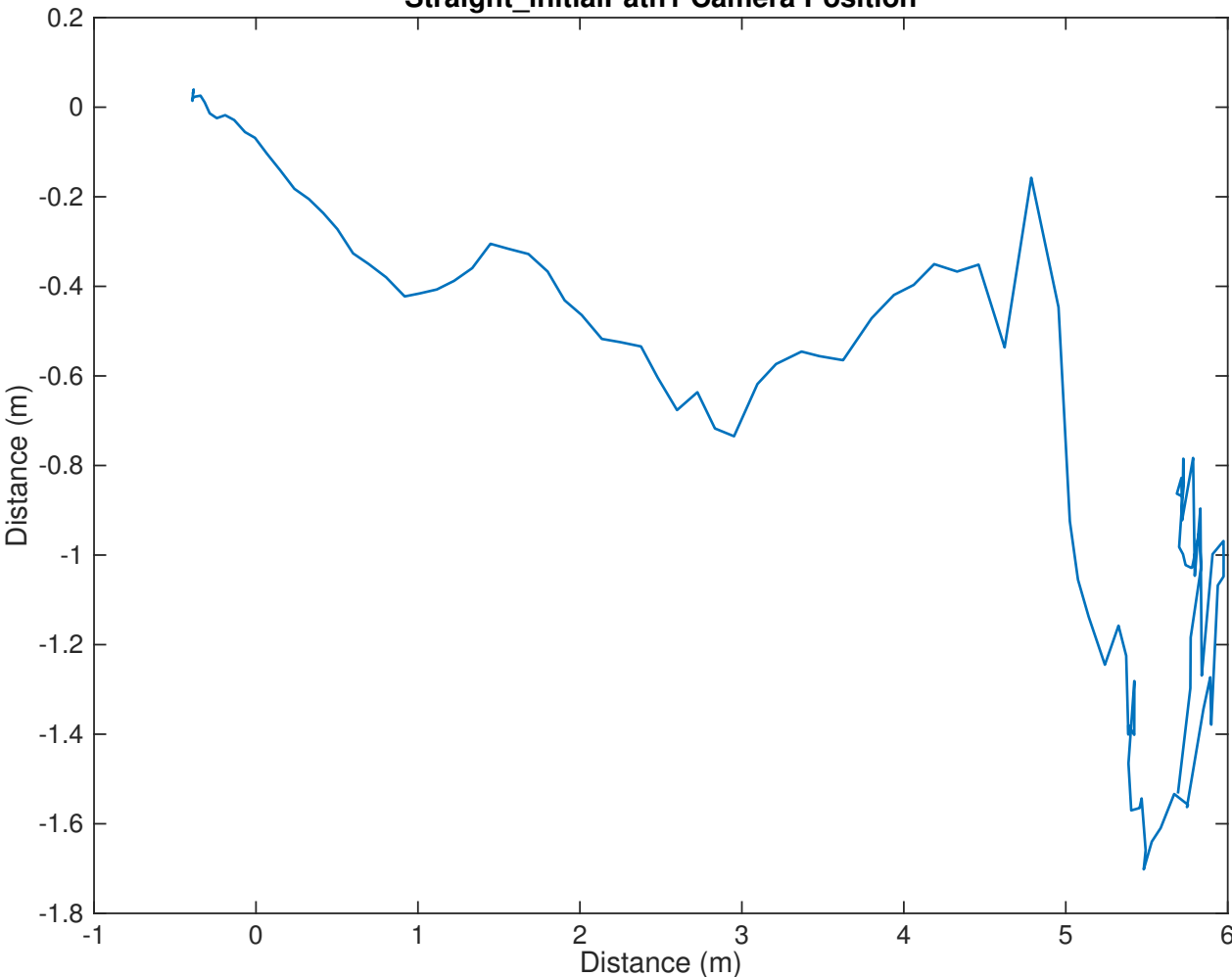
Straight\_initialPath1 Camera vs LIDAR Theta\_1



Straight\_initialPath1 Camera vs LIDAR Theta\_2

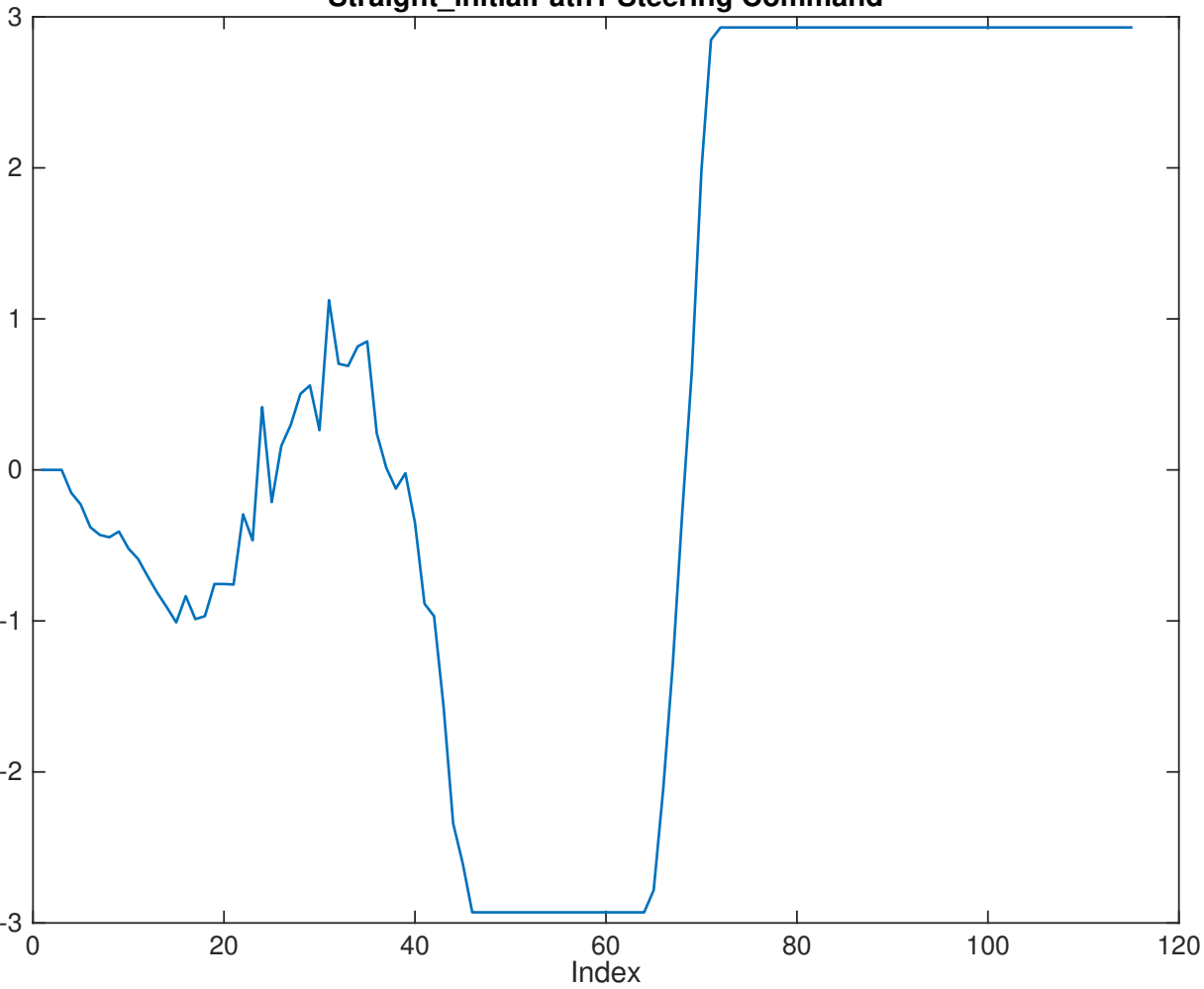


Straight\_initialPath1 Camera Position

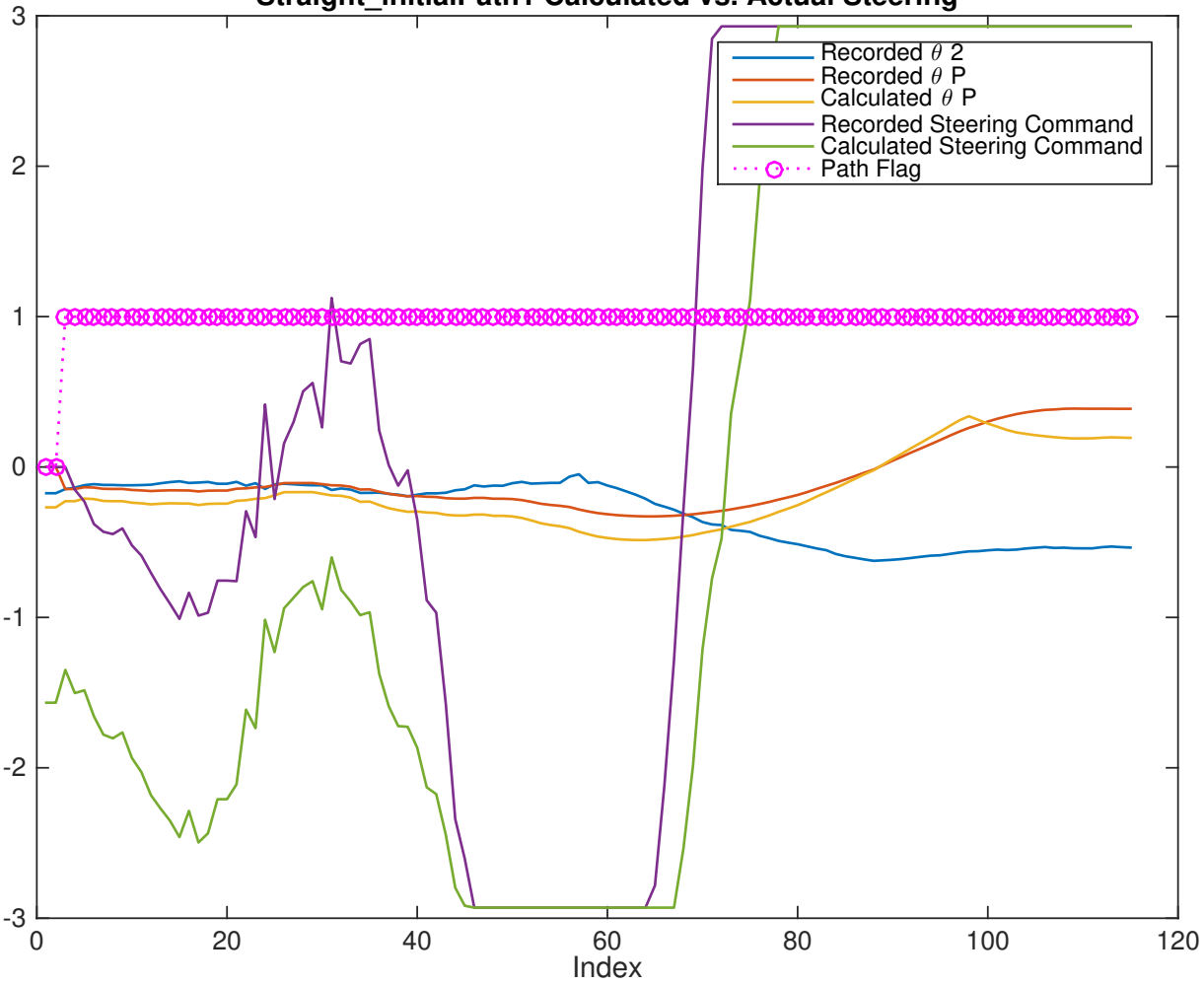


Straight\_initialPath1 Steering Command

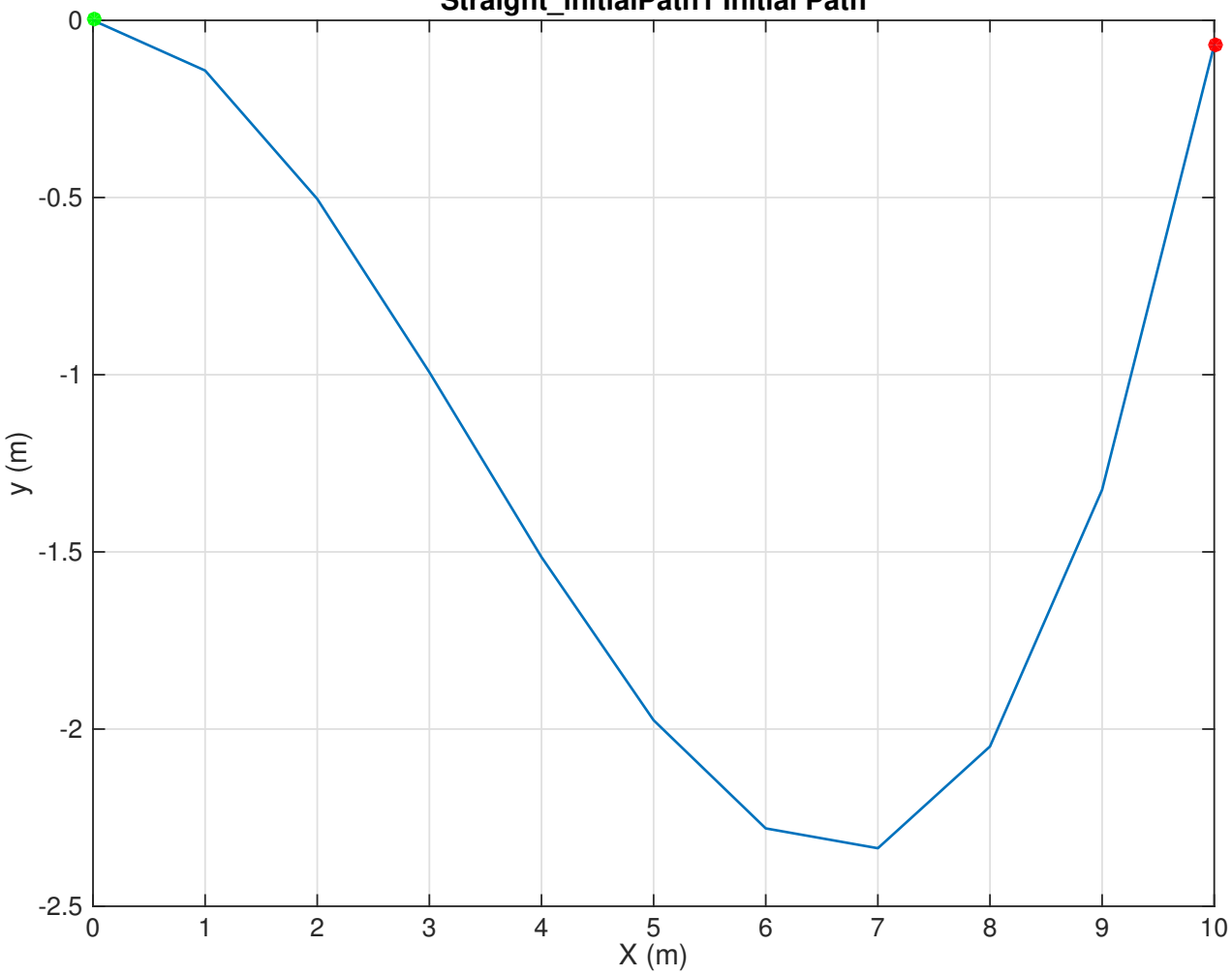
Turns (Clockwise Positive) 1 = 360° turn



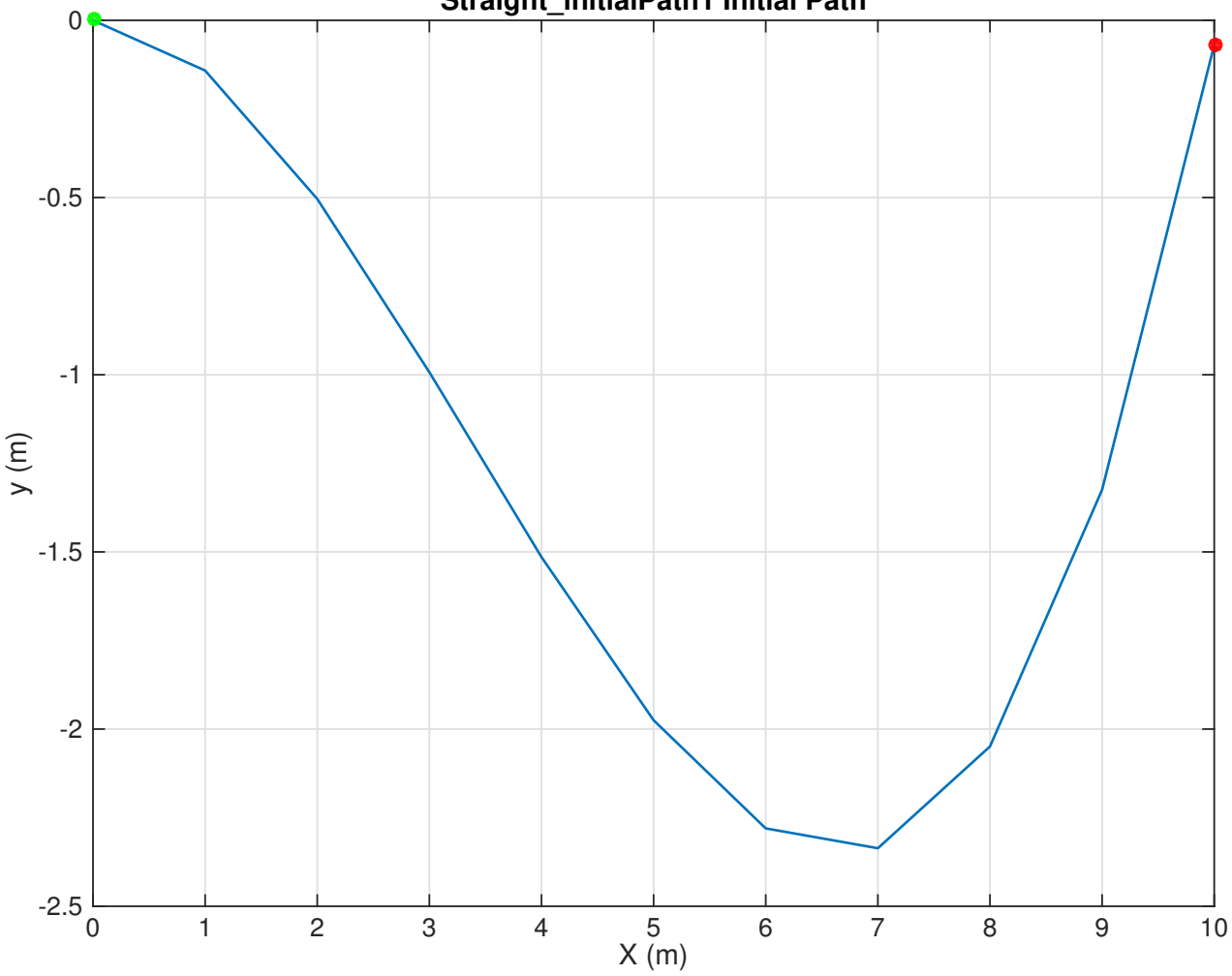
**Straight\_initialPath1 Calculated vs. Actual Steering**



Straight\_initialPath1 Initial Path

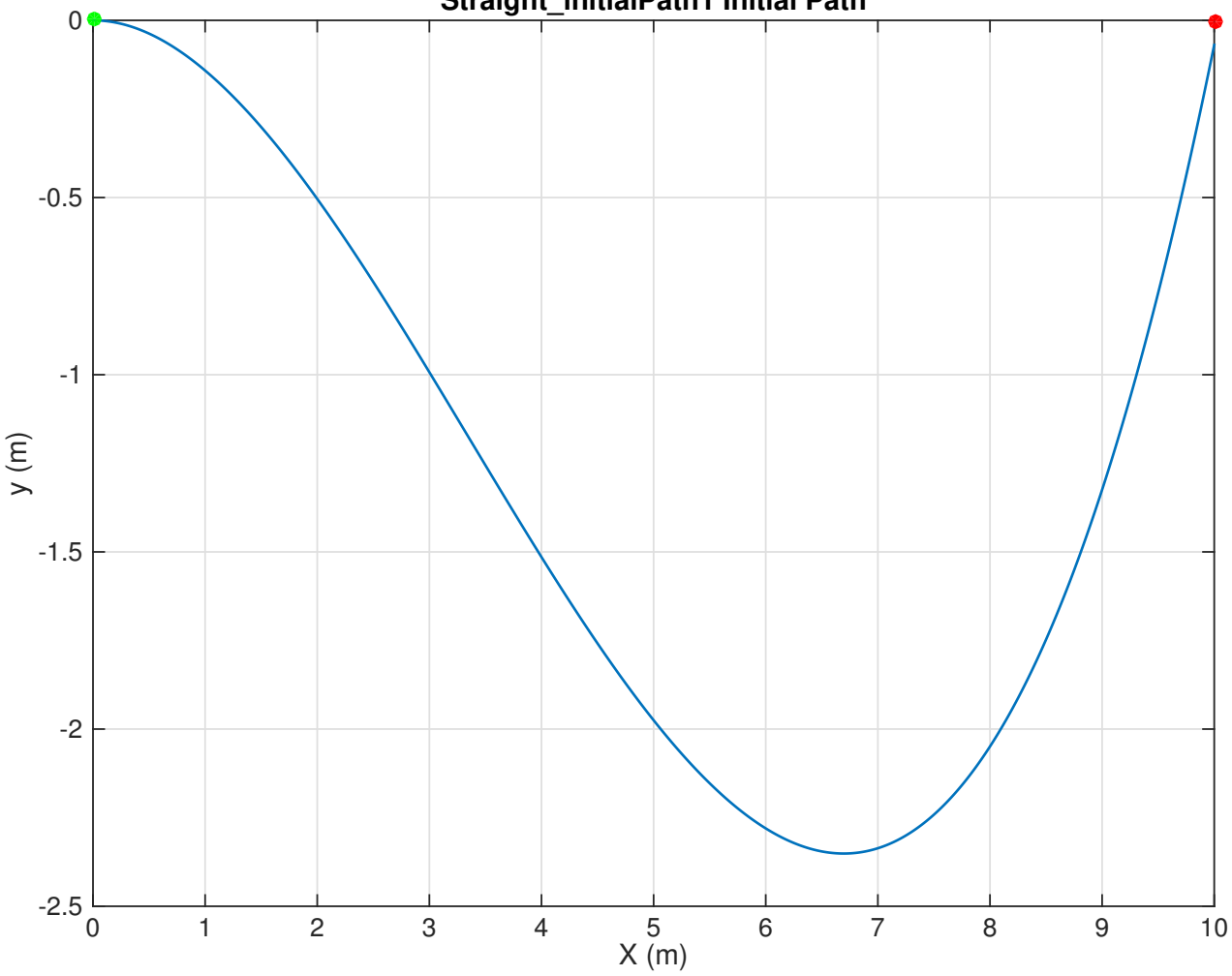


Straight\_initialPath1 Initial Path

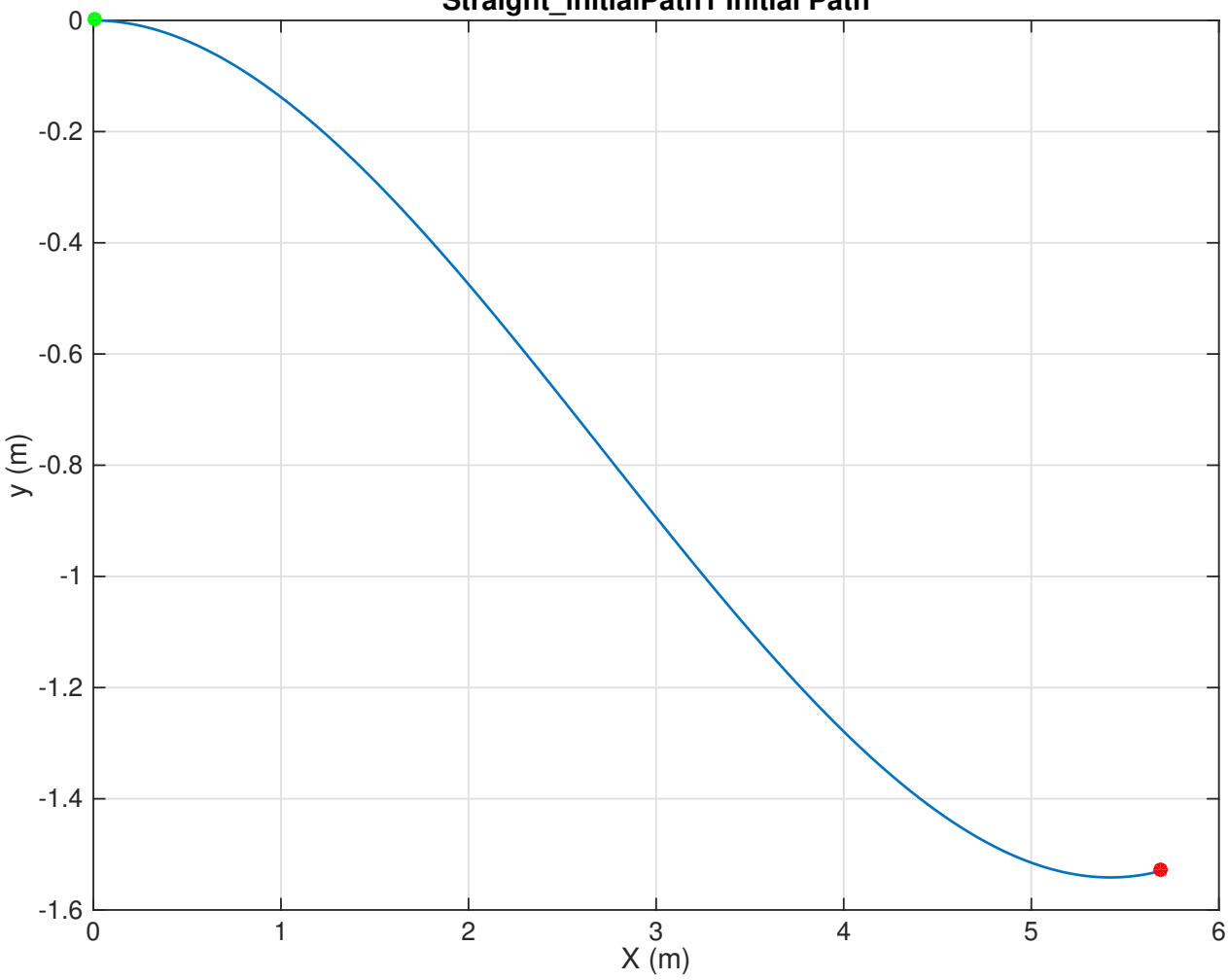




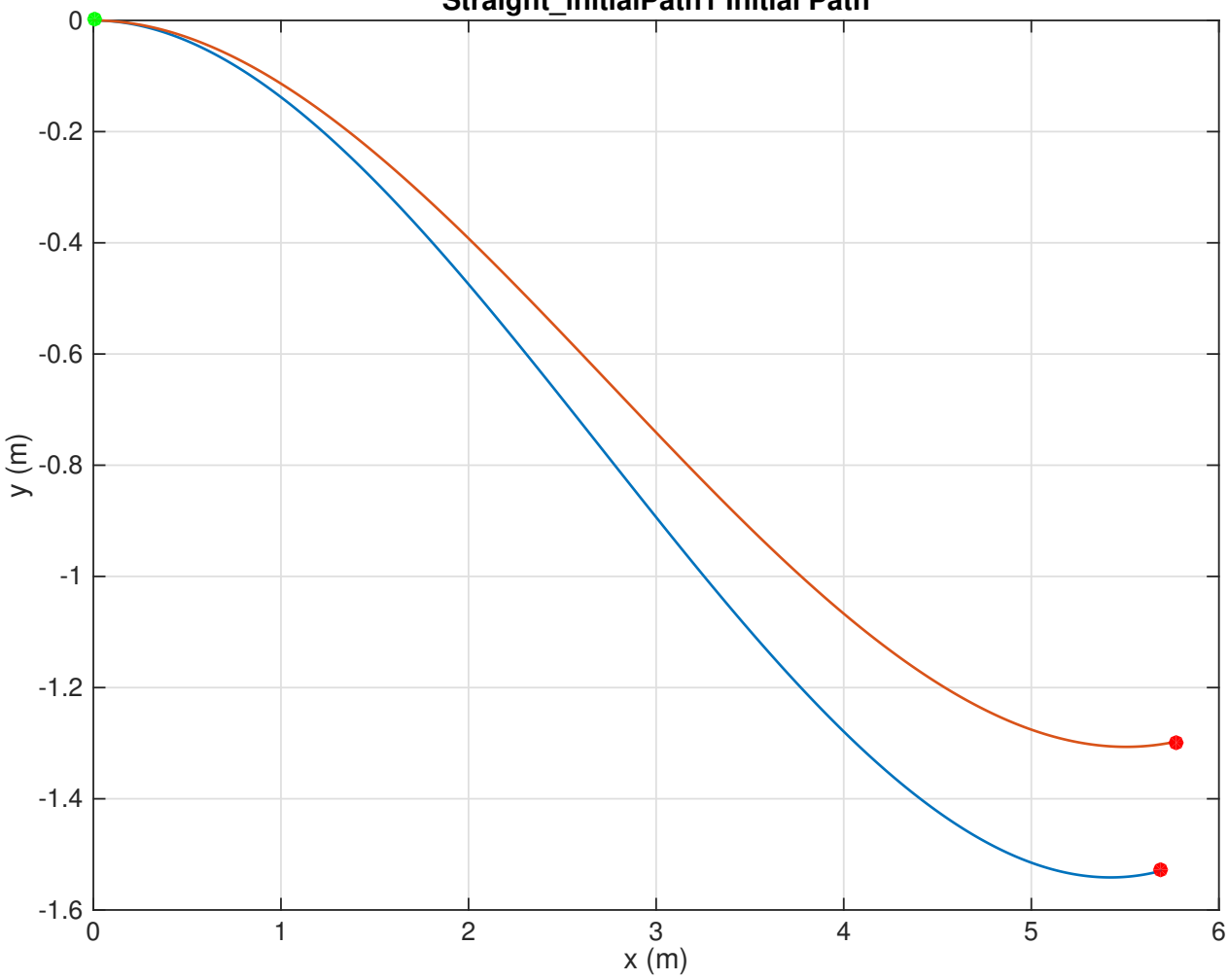
Straight\_initialPath1 Initial Path



Straight\_initialPath1 Initial Path



Straight\_initialPath1 Initial Path



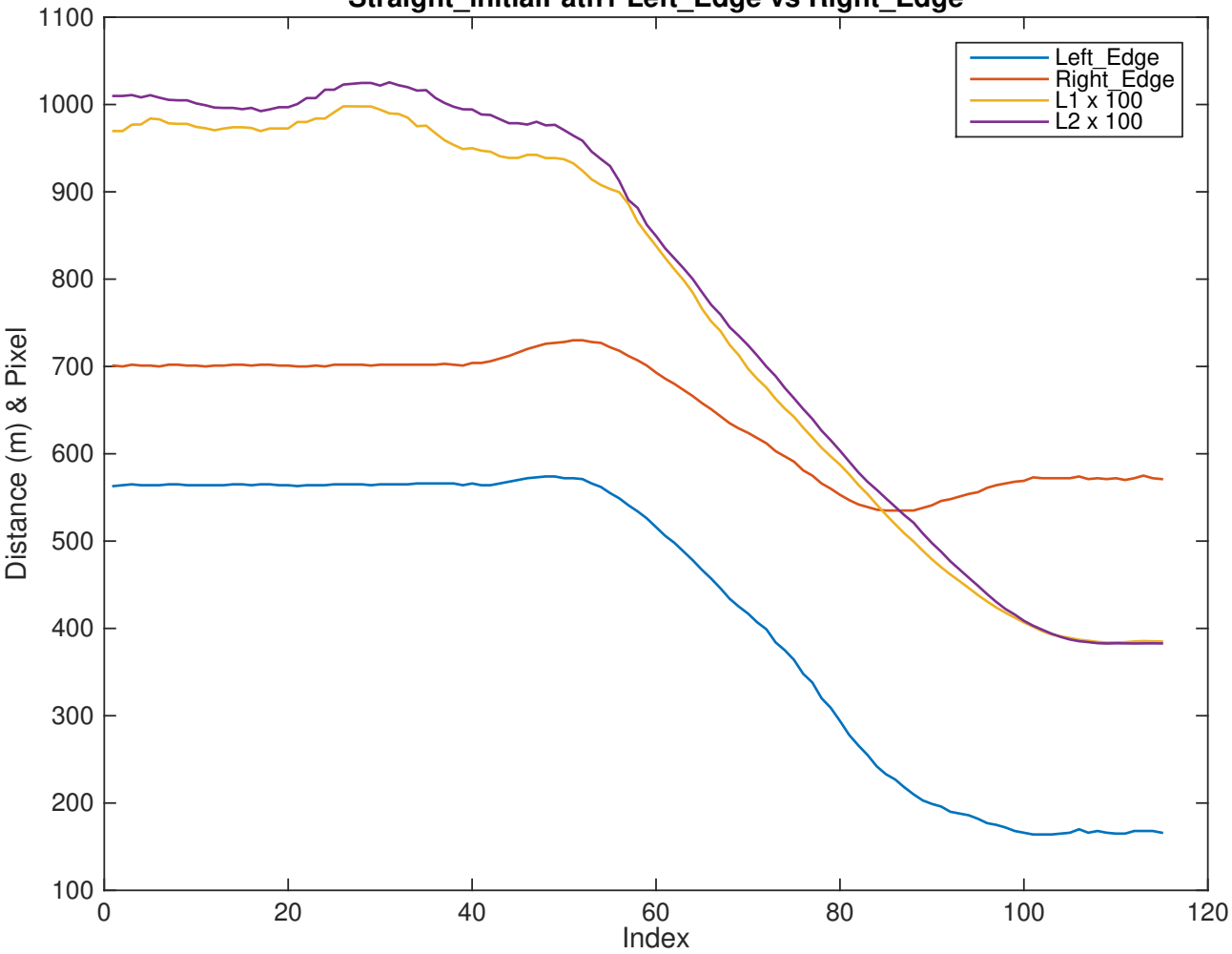
Number\_Of\_Unique\_Paths

King\_Pin\_Detected

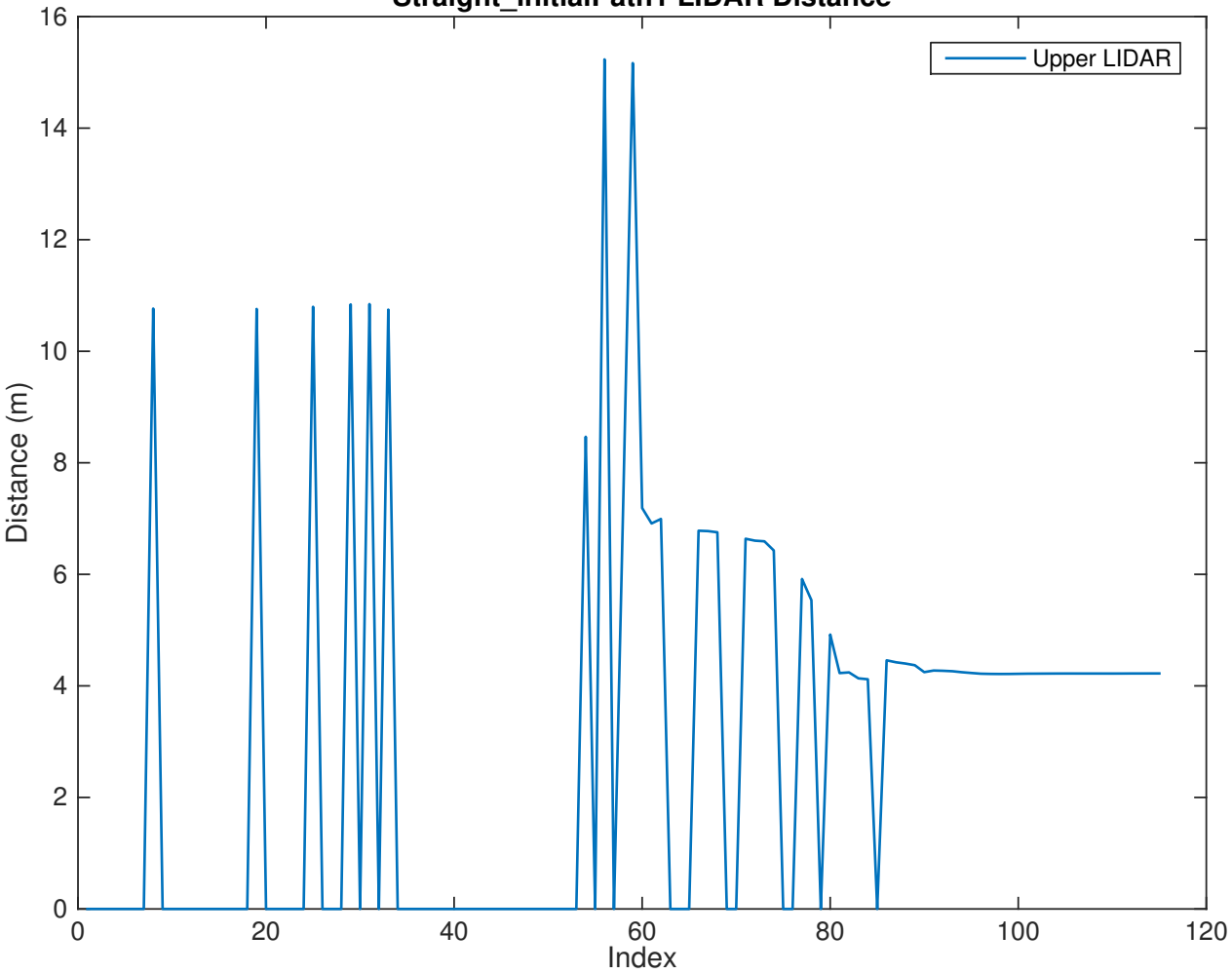
2

false

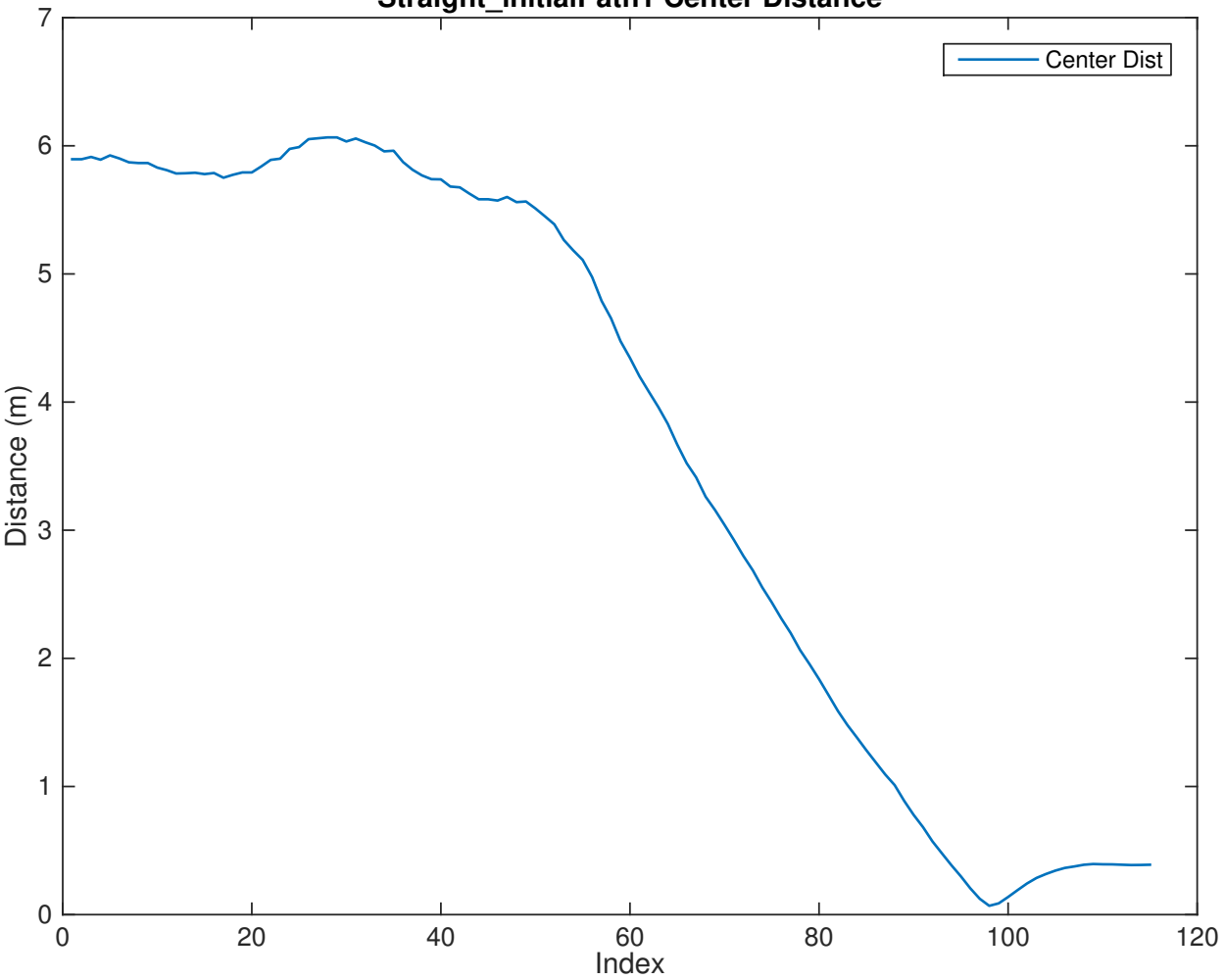
Straight\_initialPath1 Left\_Edge vs Right\_Edge



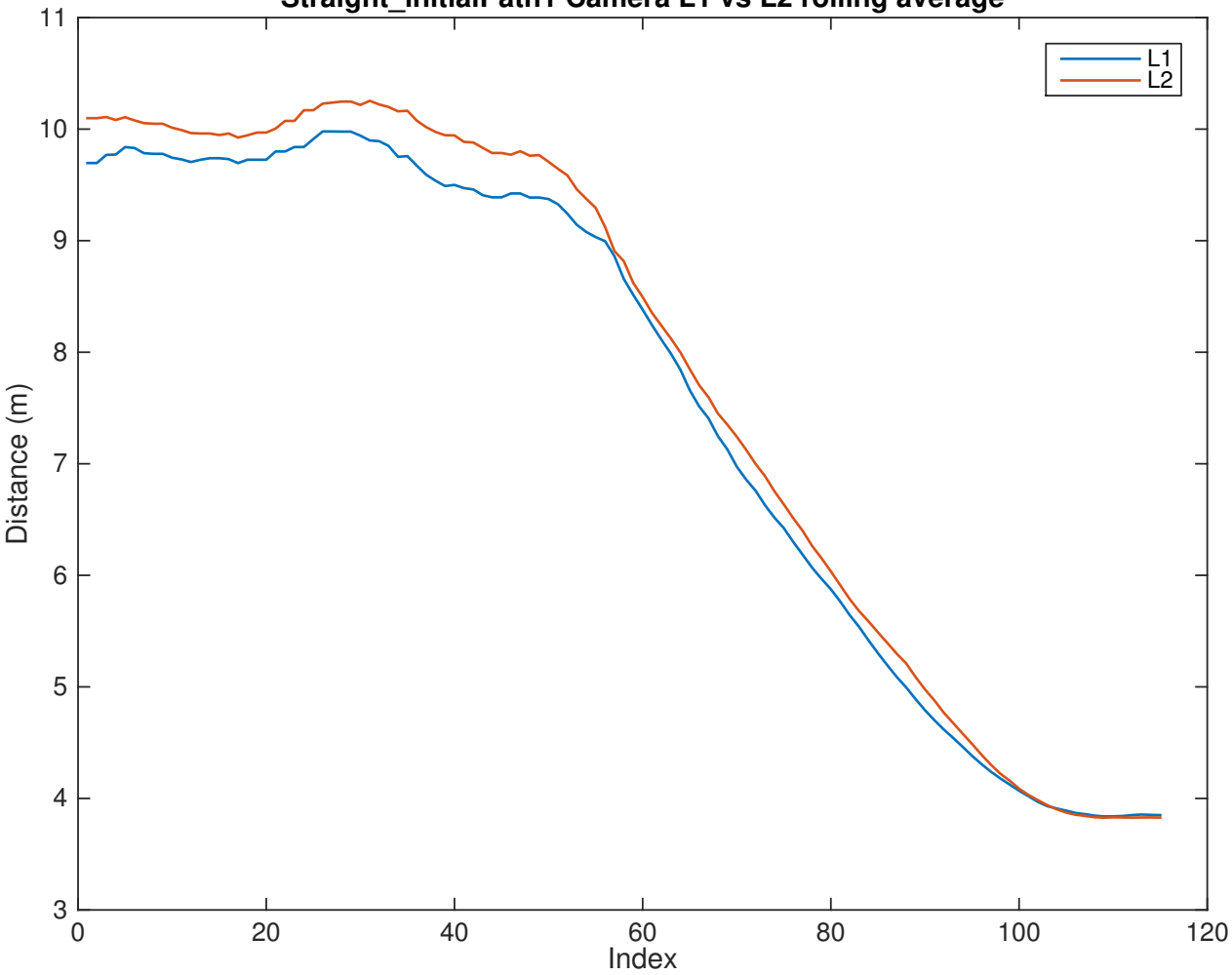
Straight\_initialPath1 LIDAR Distance



Straight\_initialPath1 Center Distance

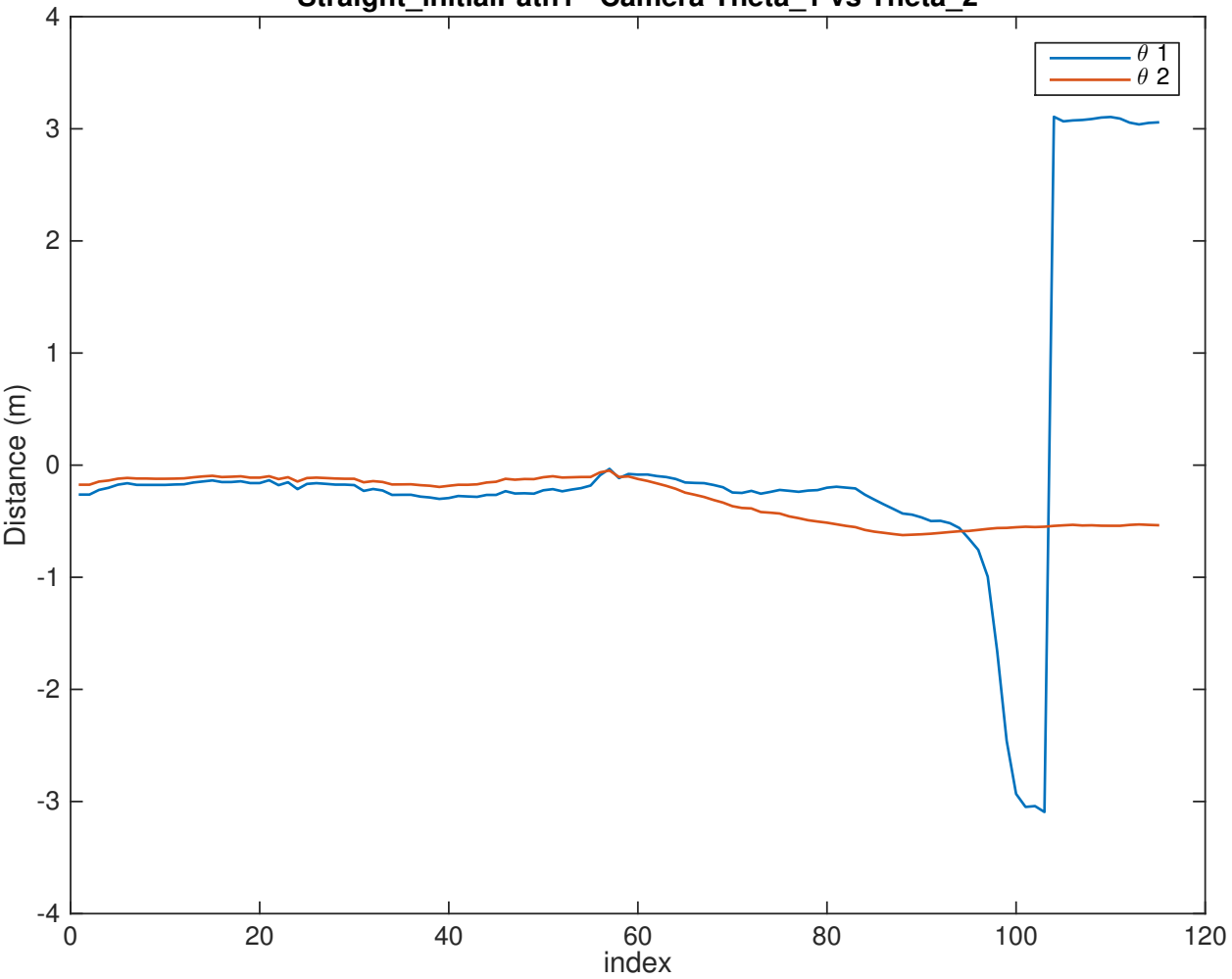


Straight\_initialPath1 Camera L1 vs L2 rolling average

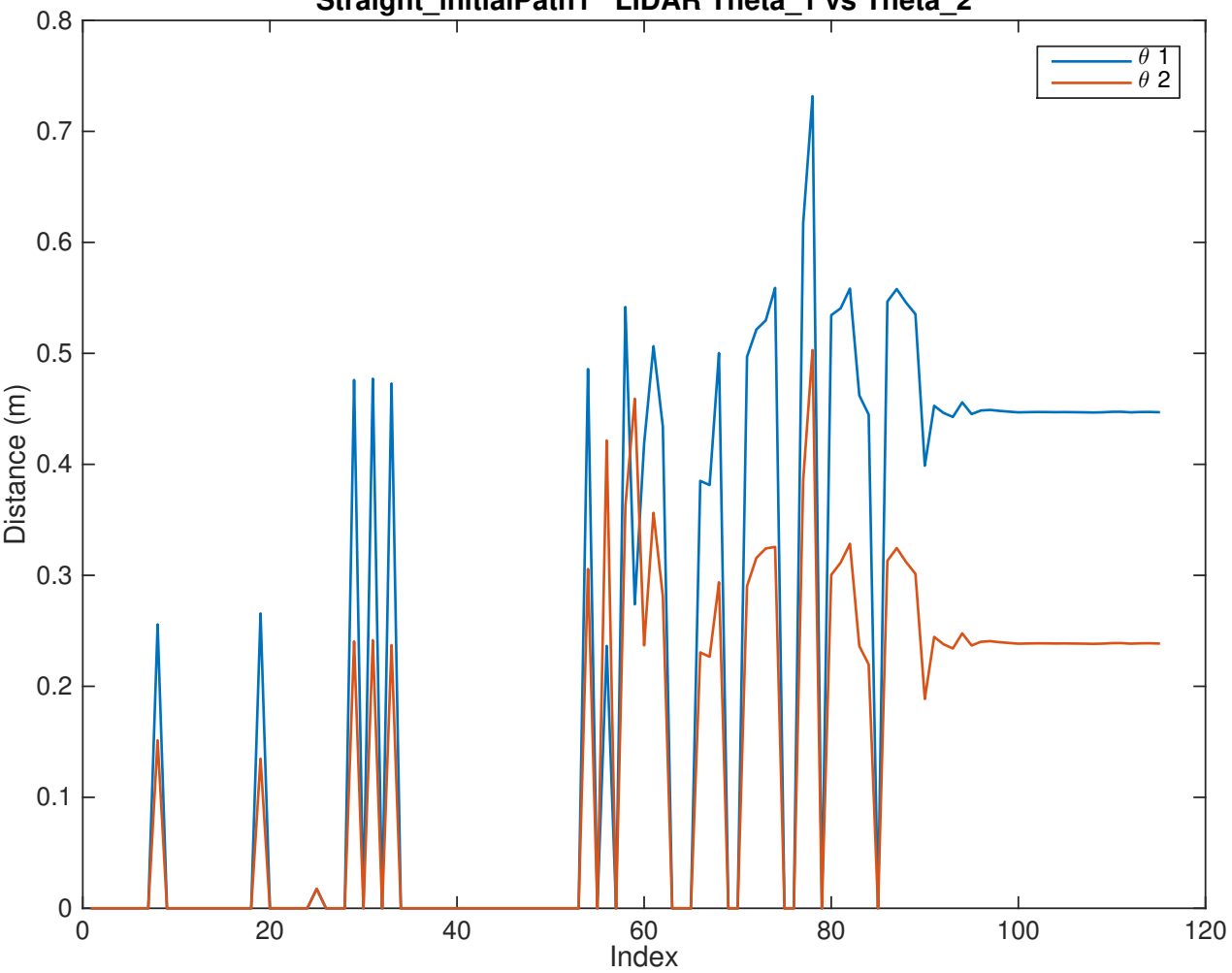




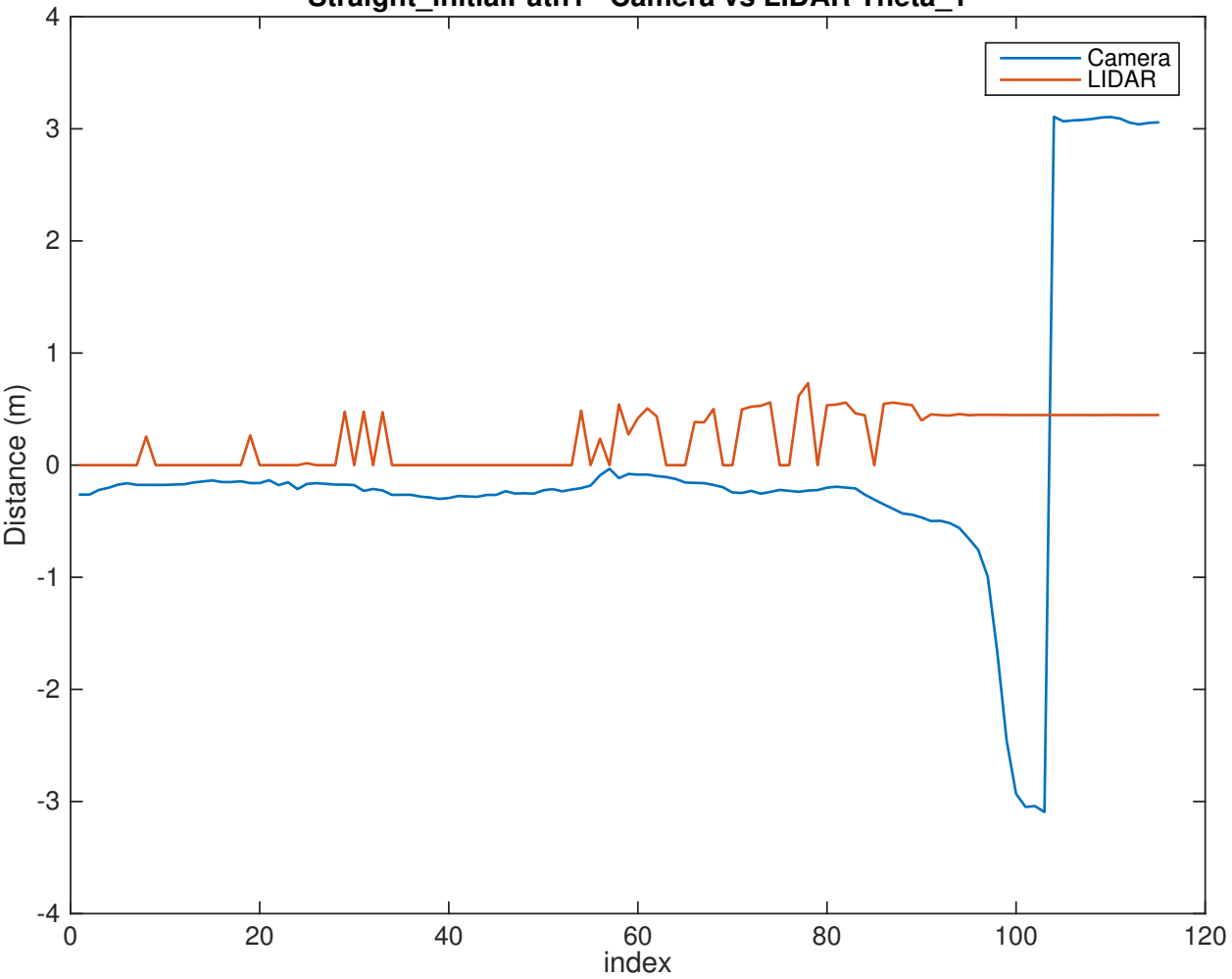
Straight\_initialPath1 Camera Theta\_1 vs Theta\_2



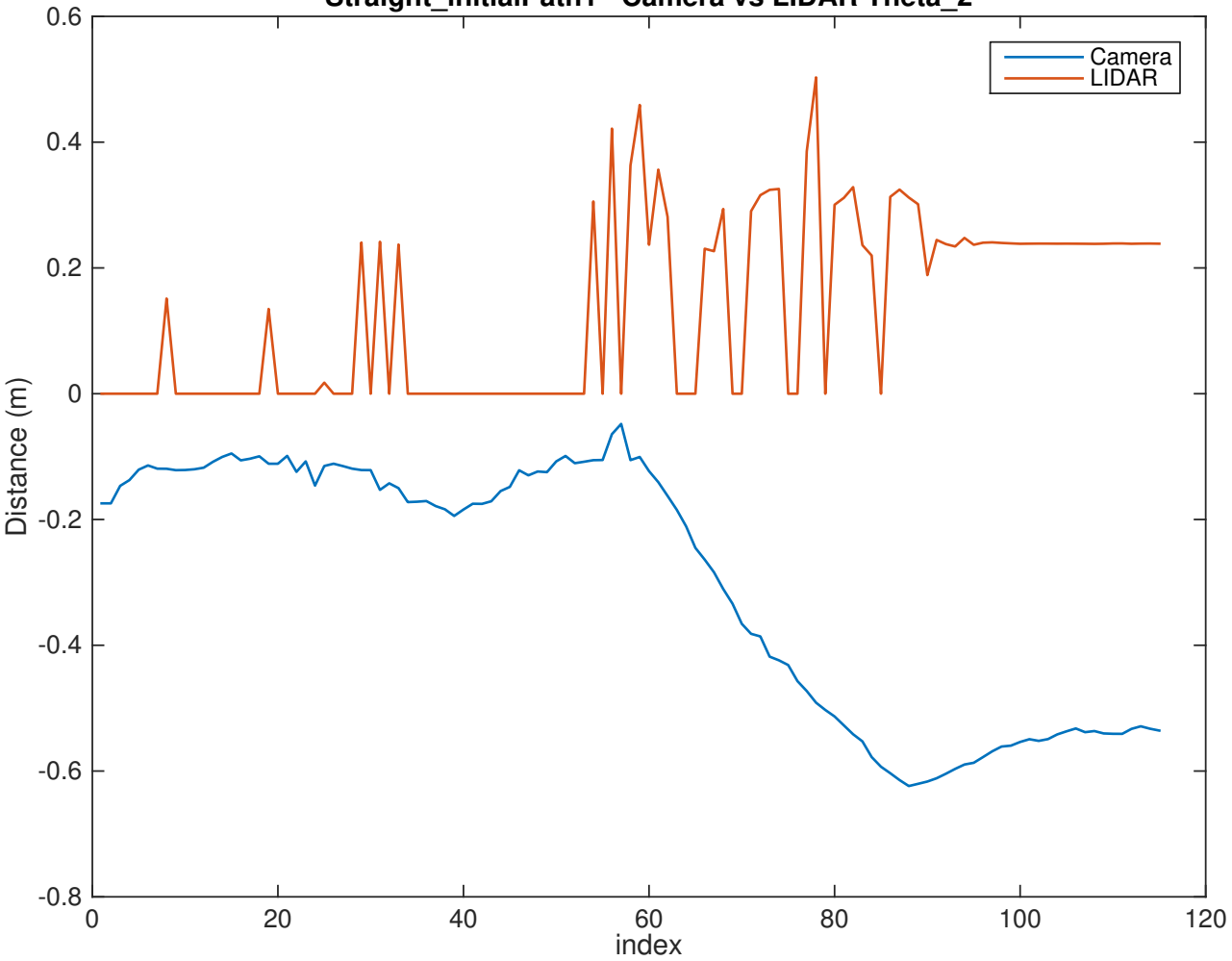
Straight\_initialPath1 LIDAR Theta\_1 vs Theta\_2



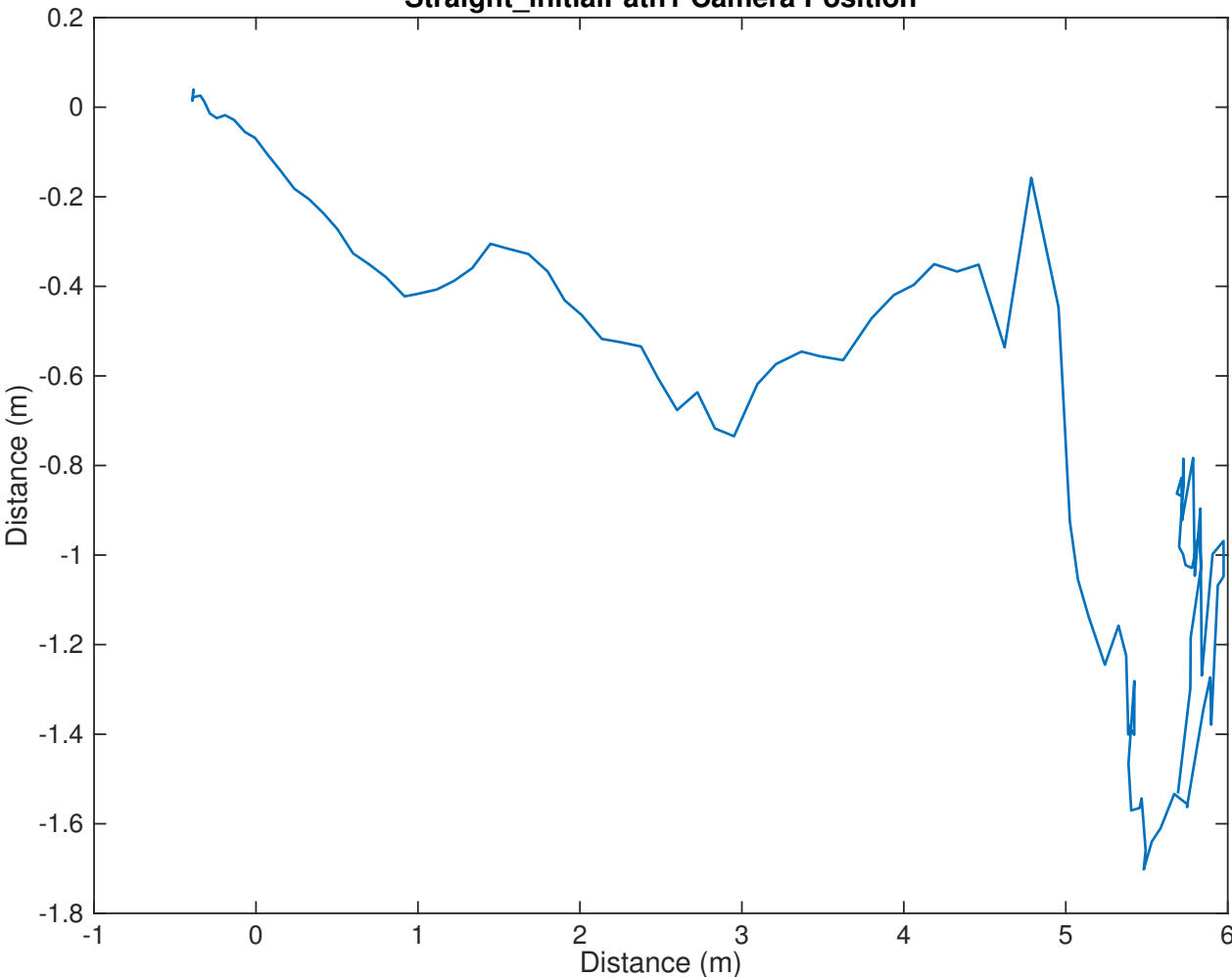
Straight\_initialPath1 Camera vs LIDAR Theta\_1



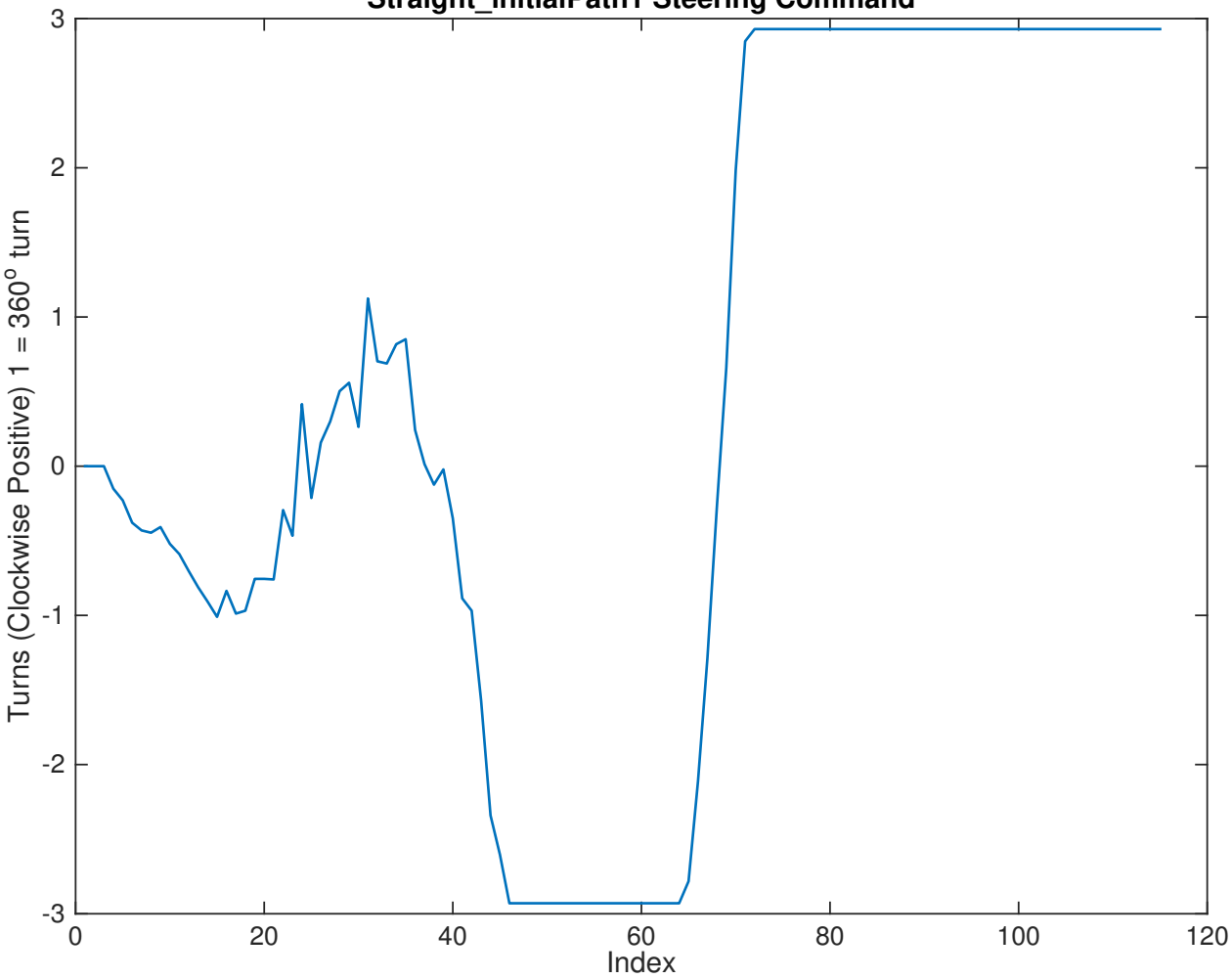
Straight\_initialPath1 Camera vs LIDAR Theta\_2



Straight\_initialPath1 Camera Position



Straight\_initialPath1 Steering Command



# Straight\_initialPath1 Calculated vs. Actual Steering

