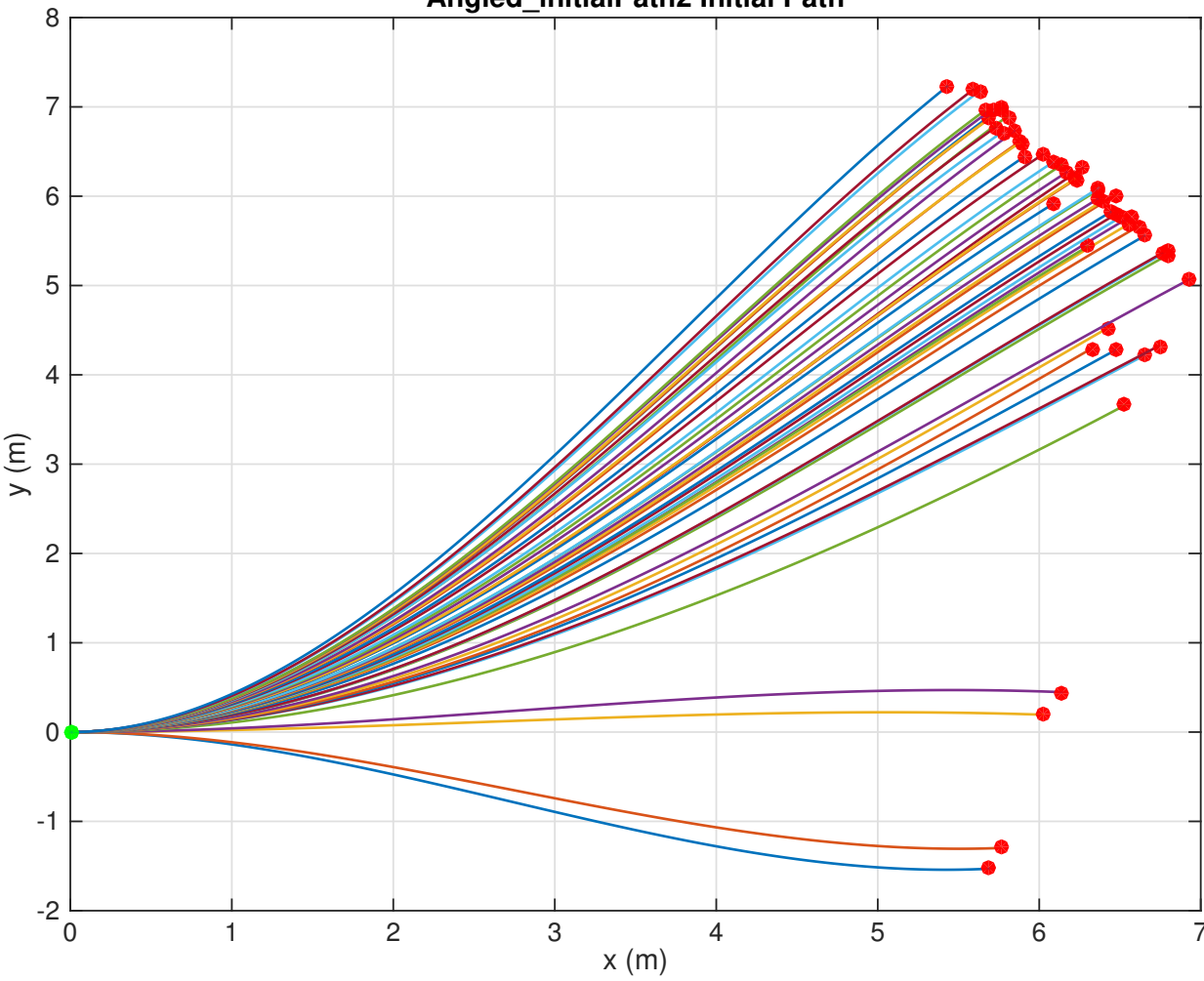


Angled_initialPath2 Initial Path



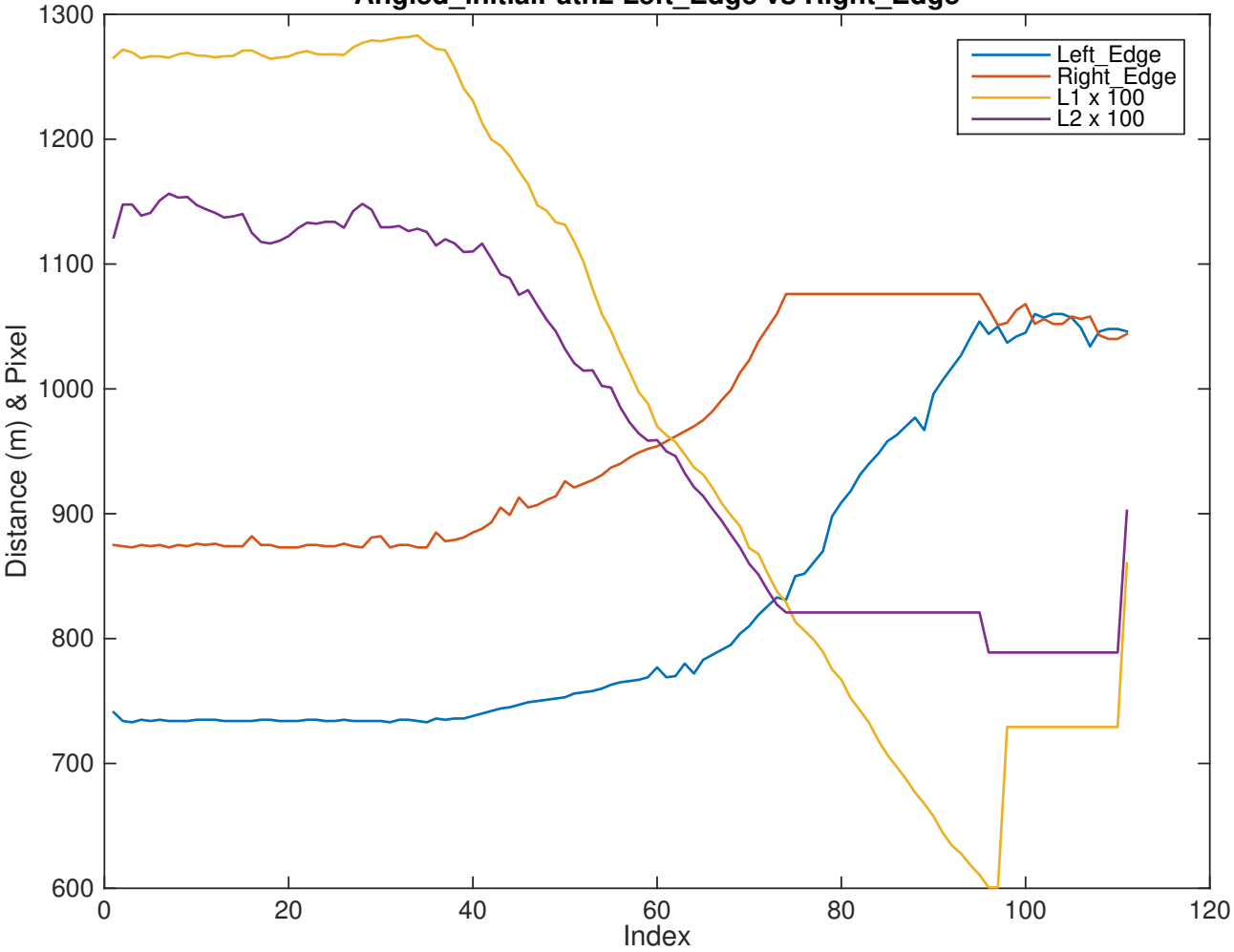
Number_Of_Unique_Paths

King_Pin_Detected

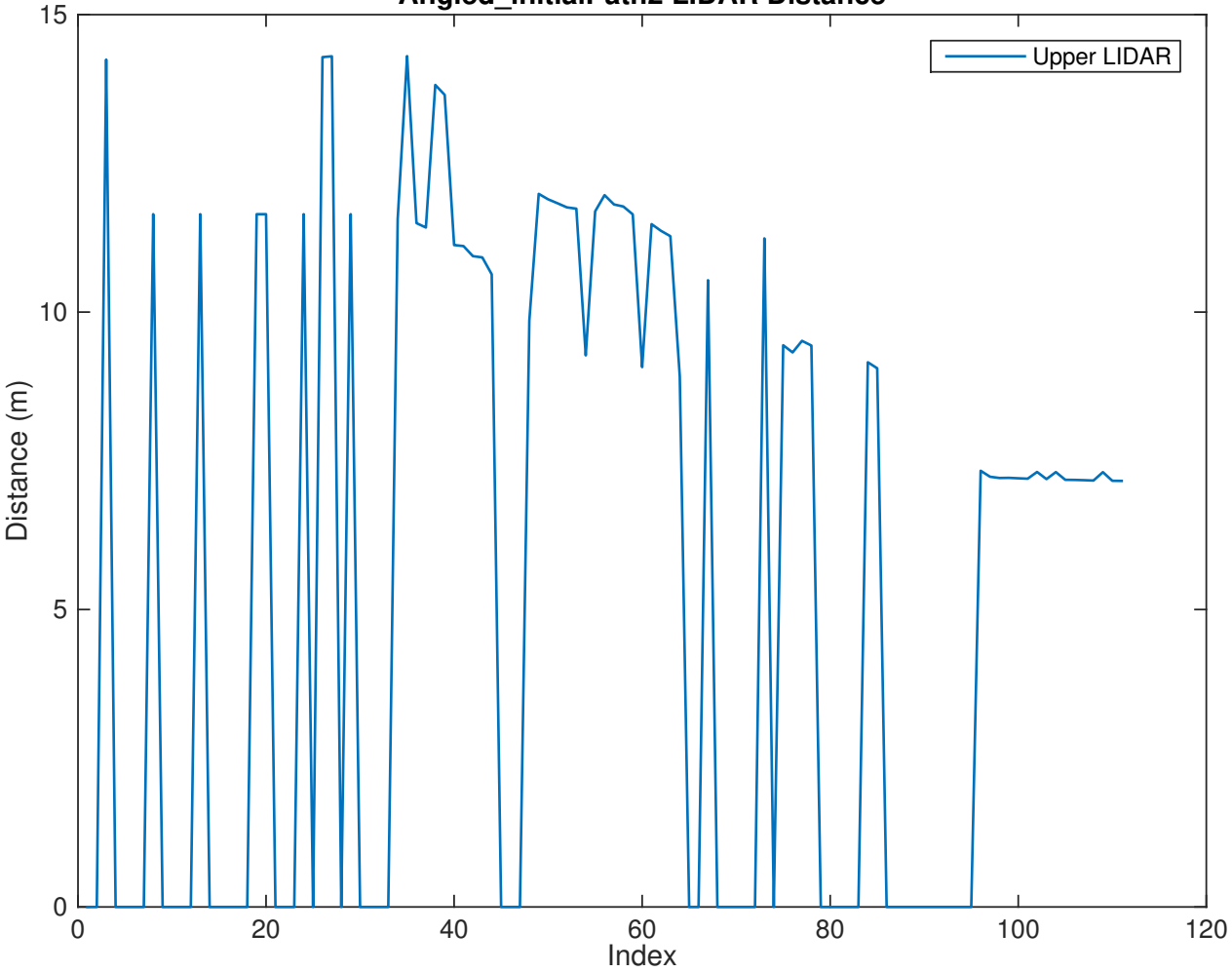
46

false

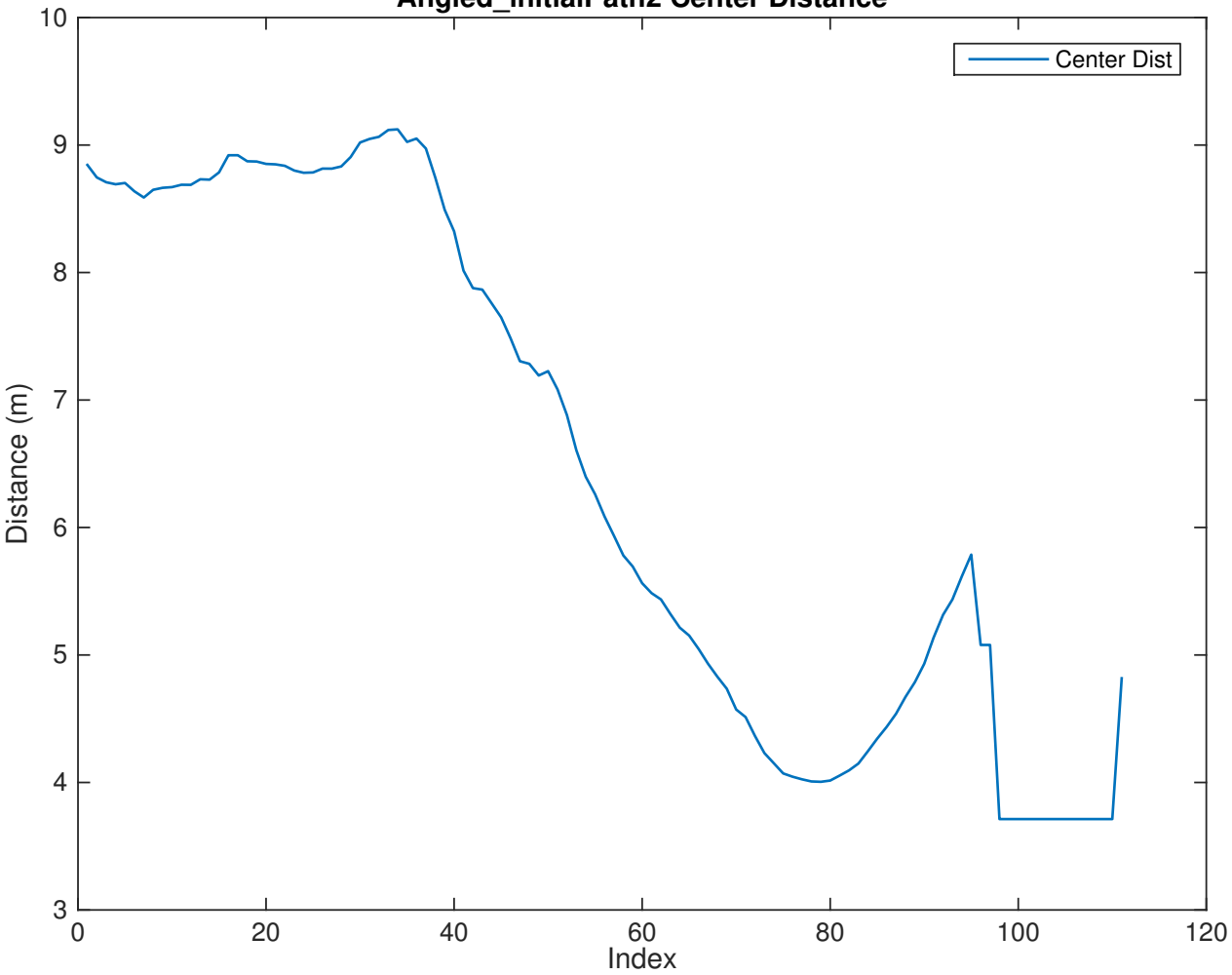
Angled_initialPath2 Left_Edge vs Right_Edge



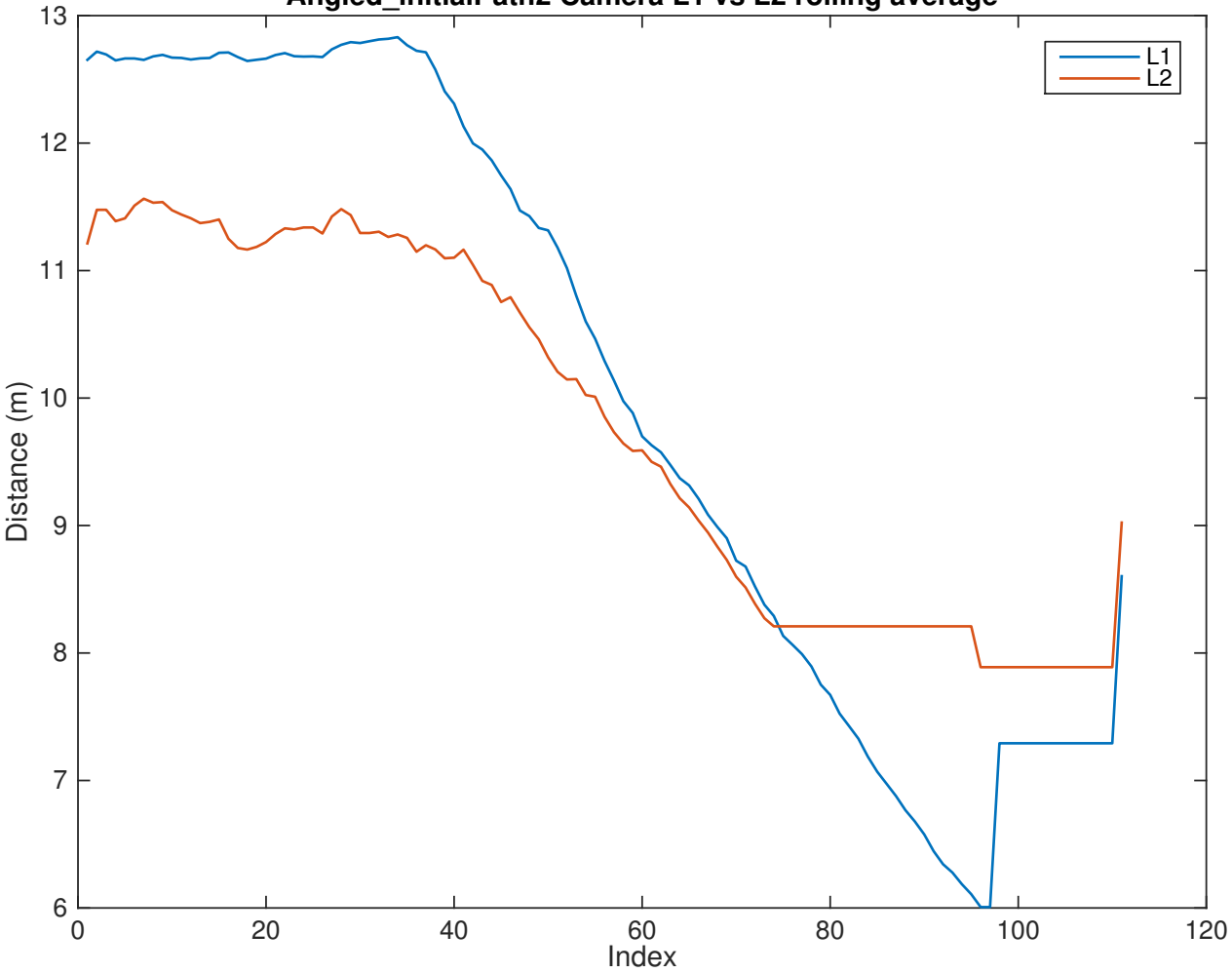
Angled_initialPath2 LIDAR Distance



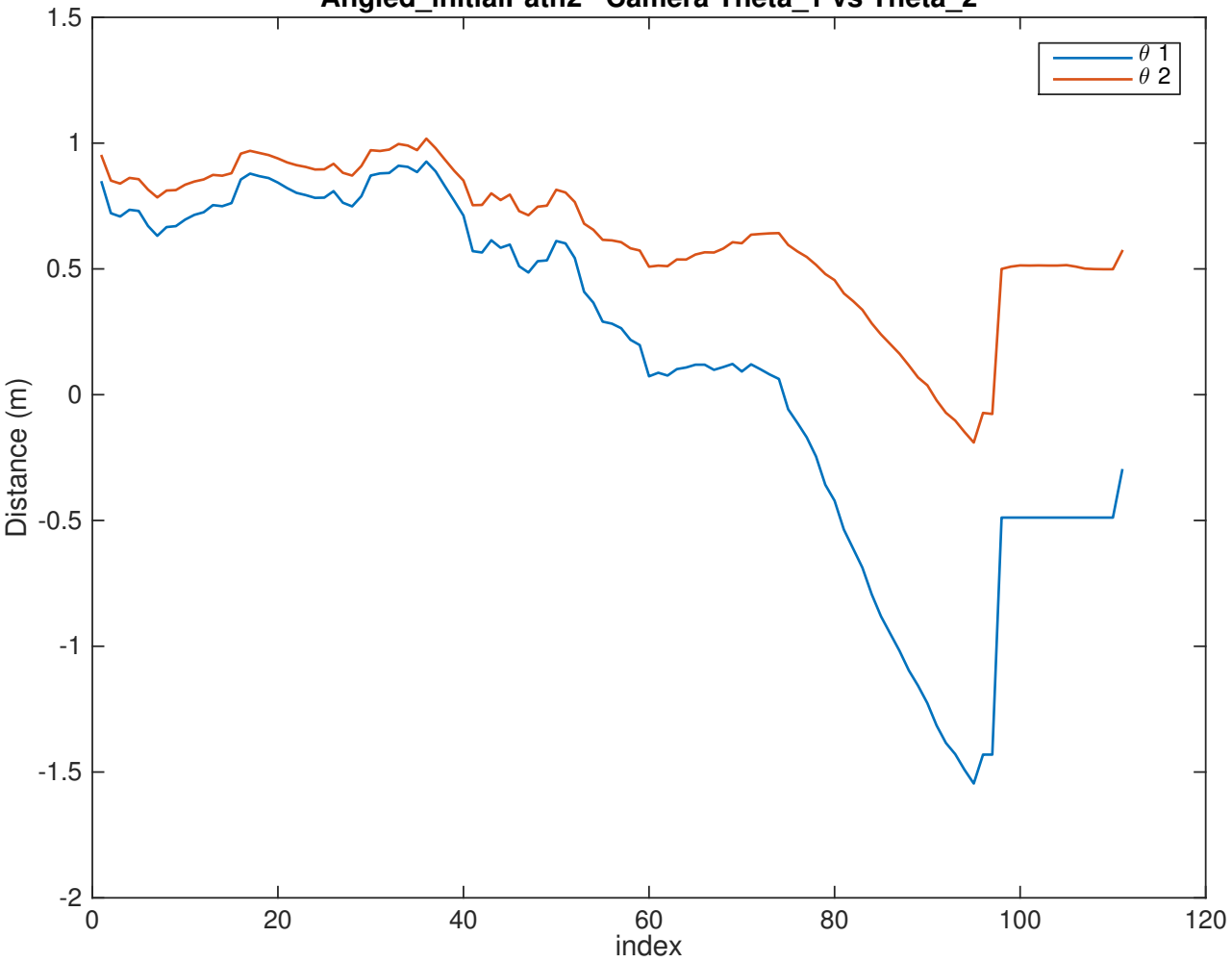
Angled_initialPath2 Center Distance



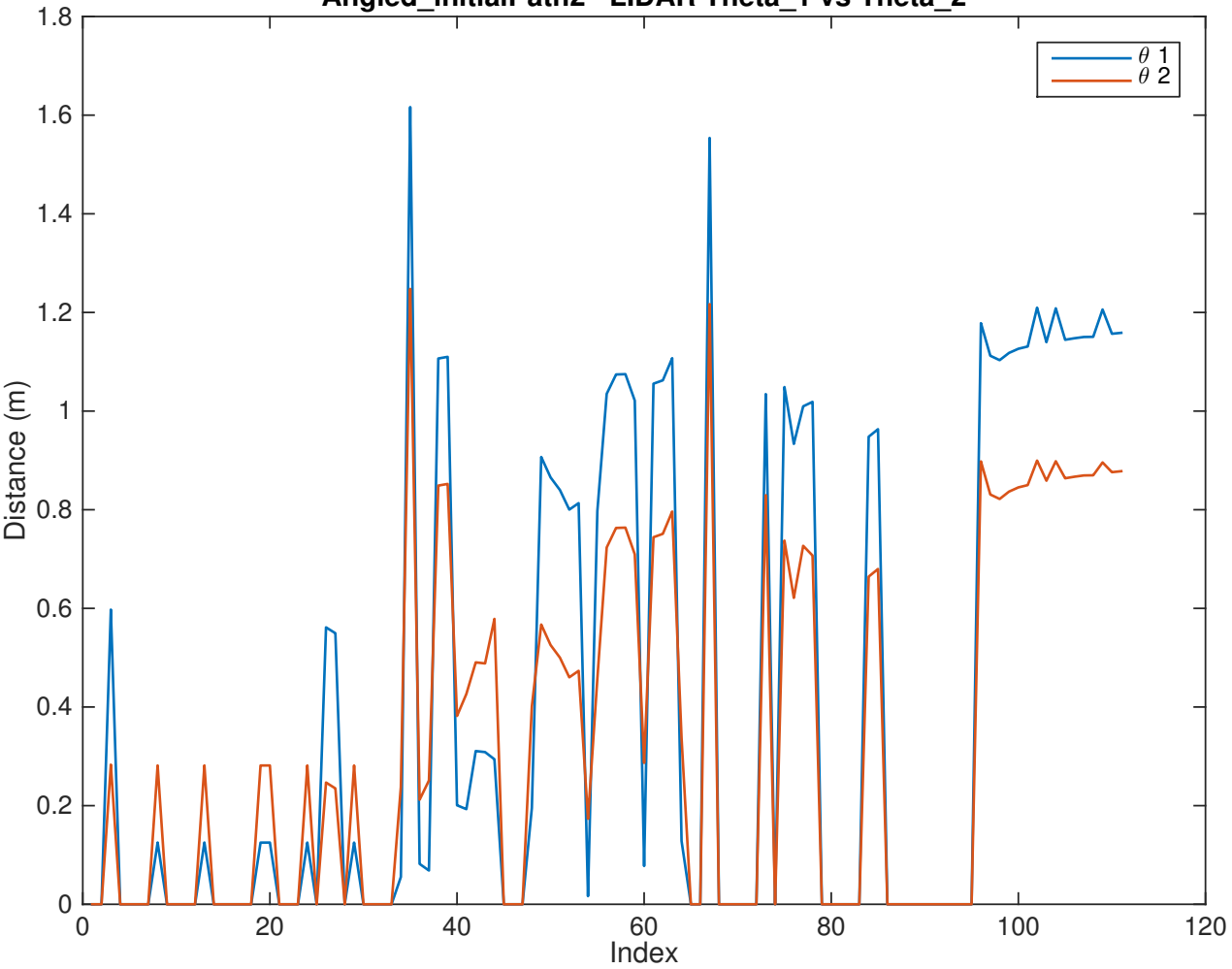
Angled_initialPath2 Camera L1 vs L2 rolling average



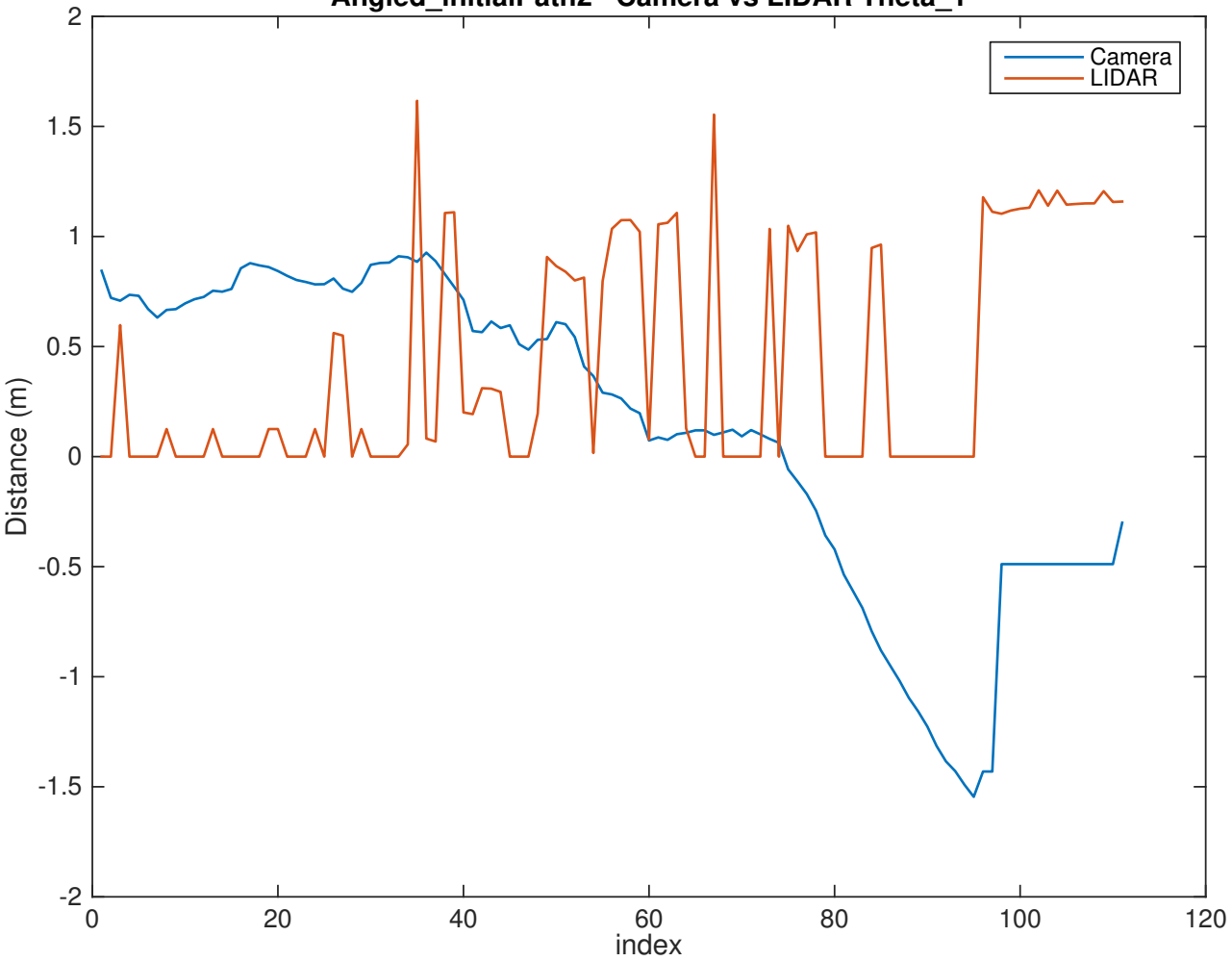
Angled_initialPath2 Camera Theta_1 vs Theta_2



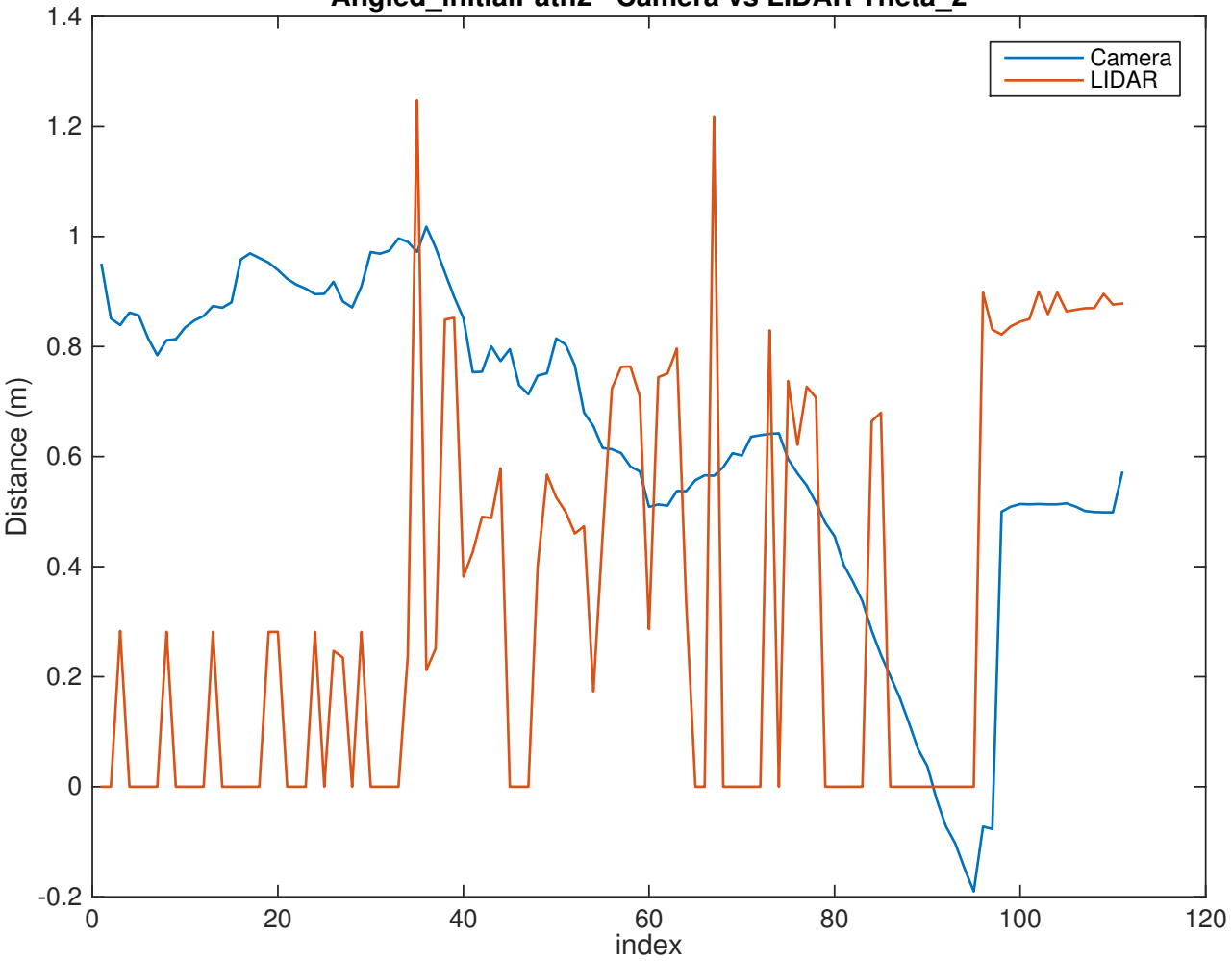
Angled_initialPath2 LIDAR Theta_1 vs Theta_2



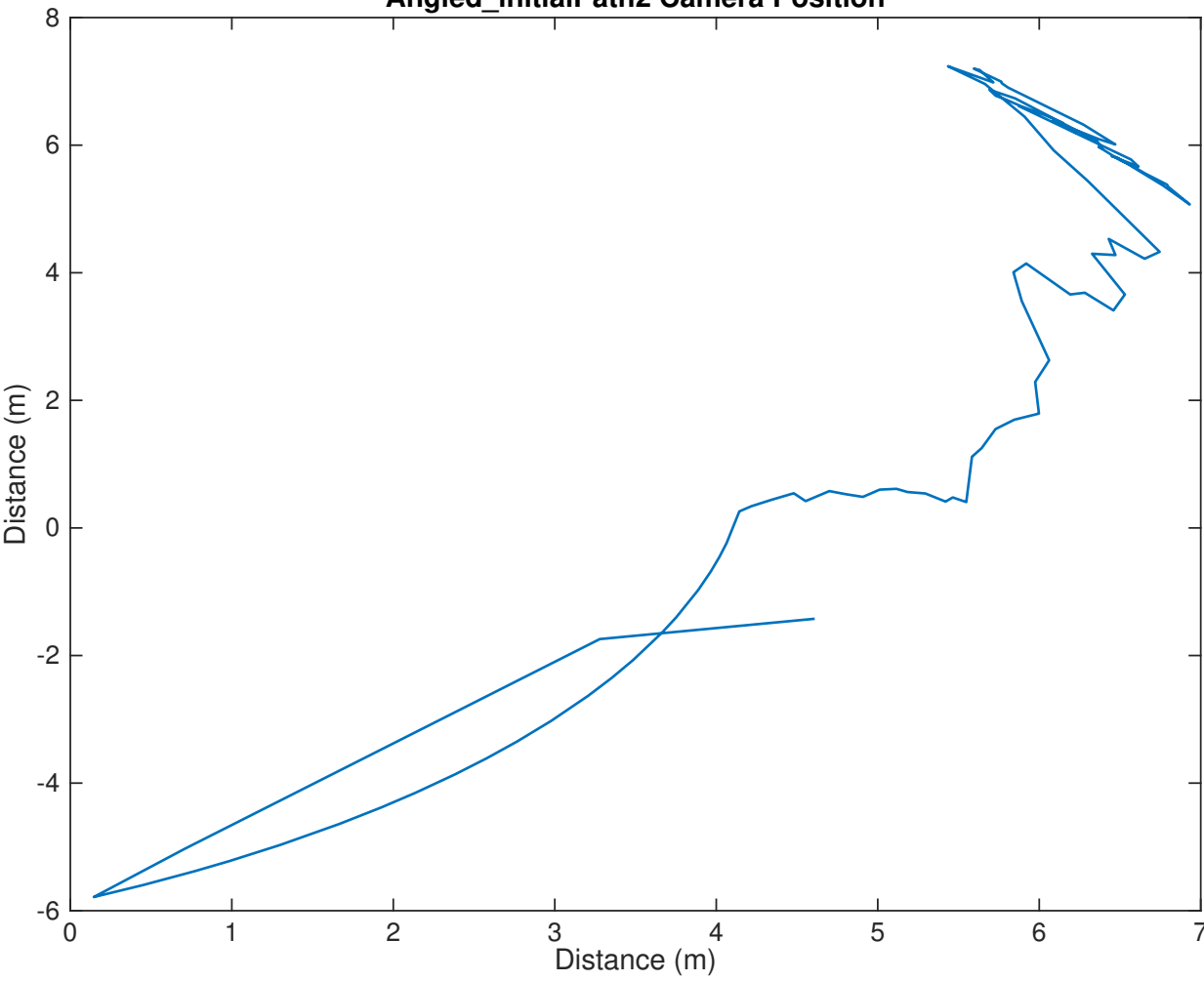
Angled_initialPath2 Camera vs LIDAR Theta_1



Angled_initialPath2 Camera vs LIDAR Theta_2

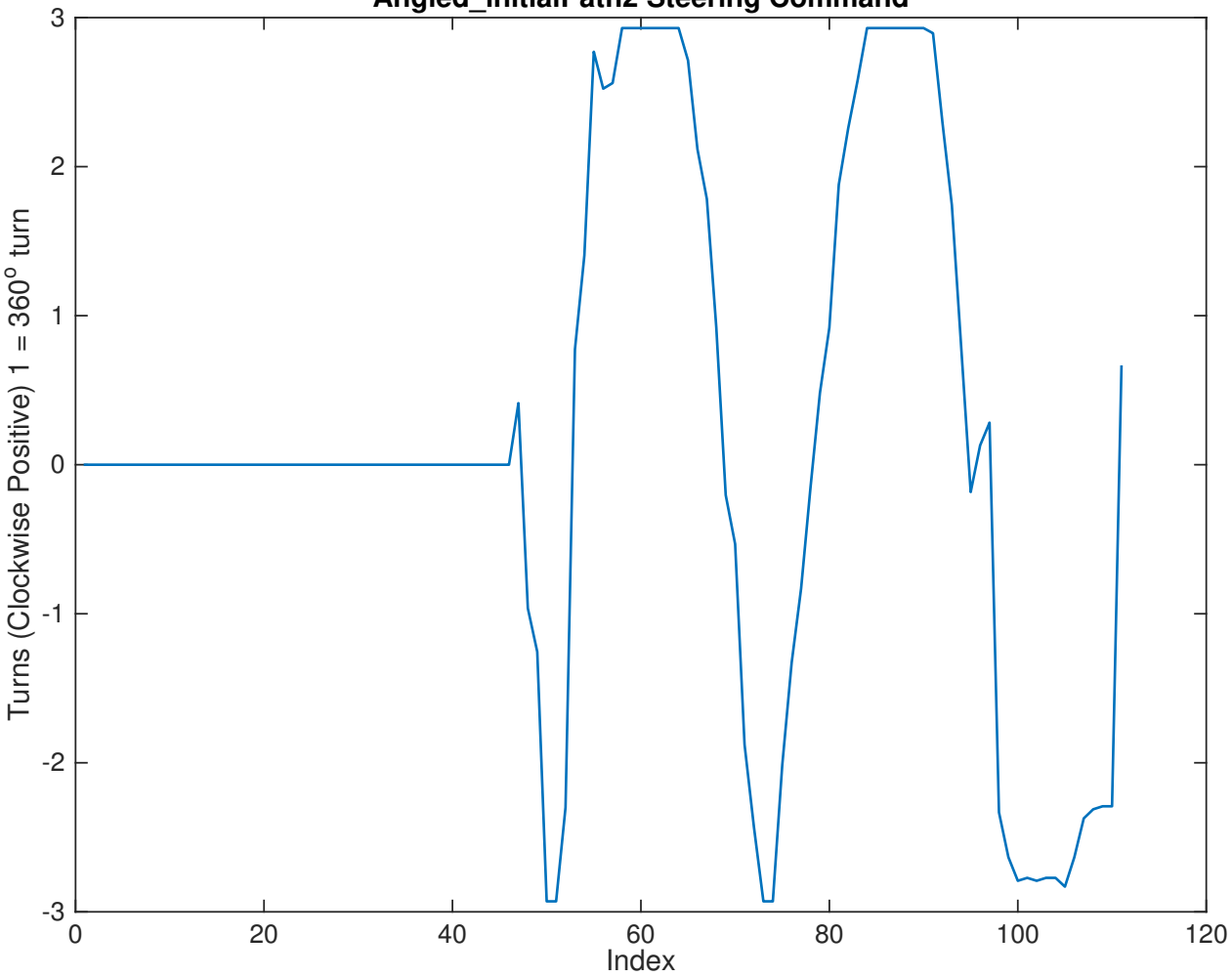


Angled_initialPath2 Camera Position



Angled_initialPath2 Steering Command

Turns (Clockwise Positive) 1 = 360° turn



Angled_initialPath2 Calculated vs. Actual Steering

