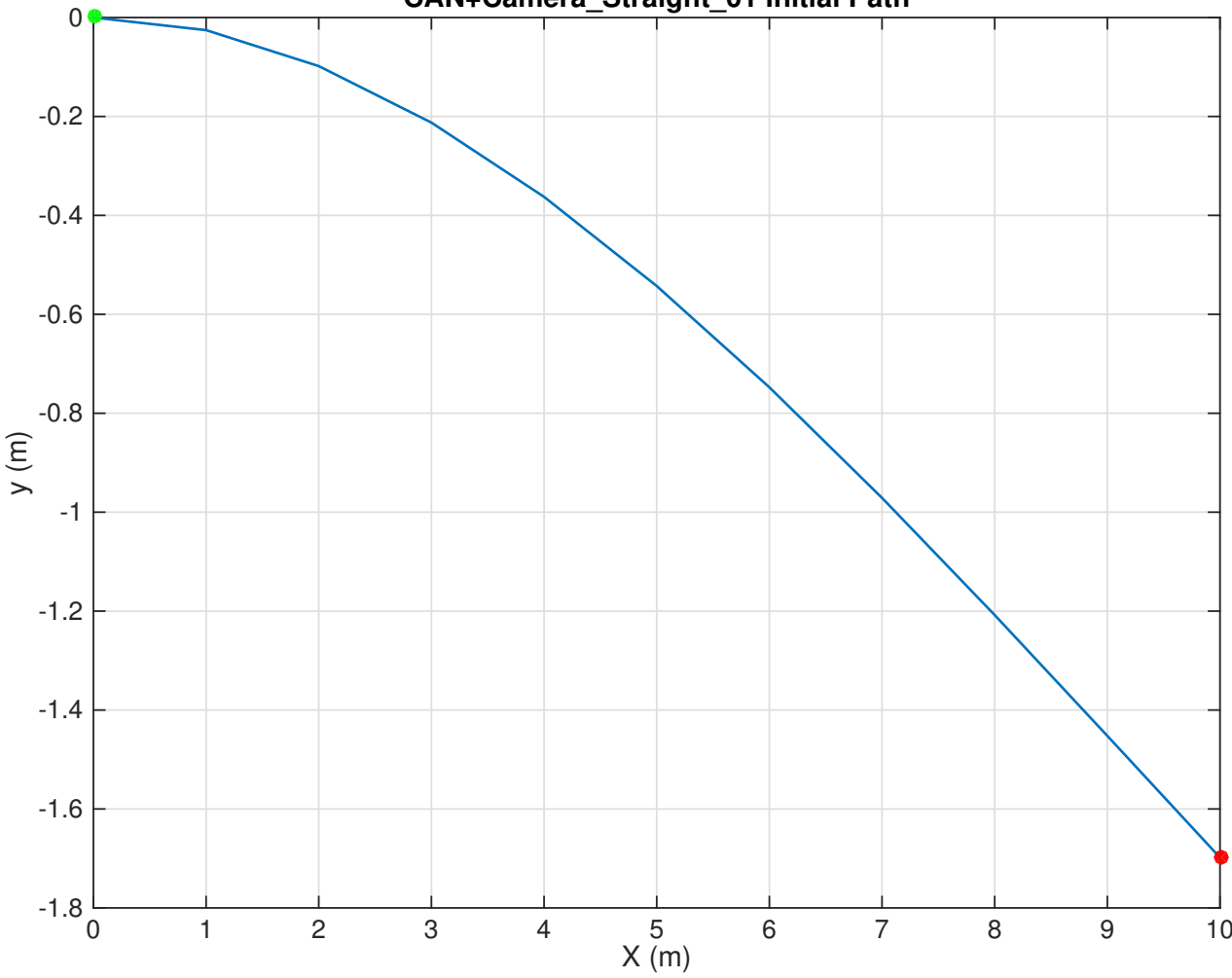
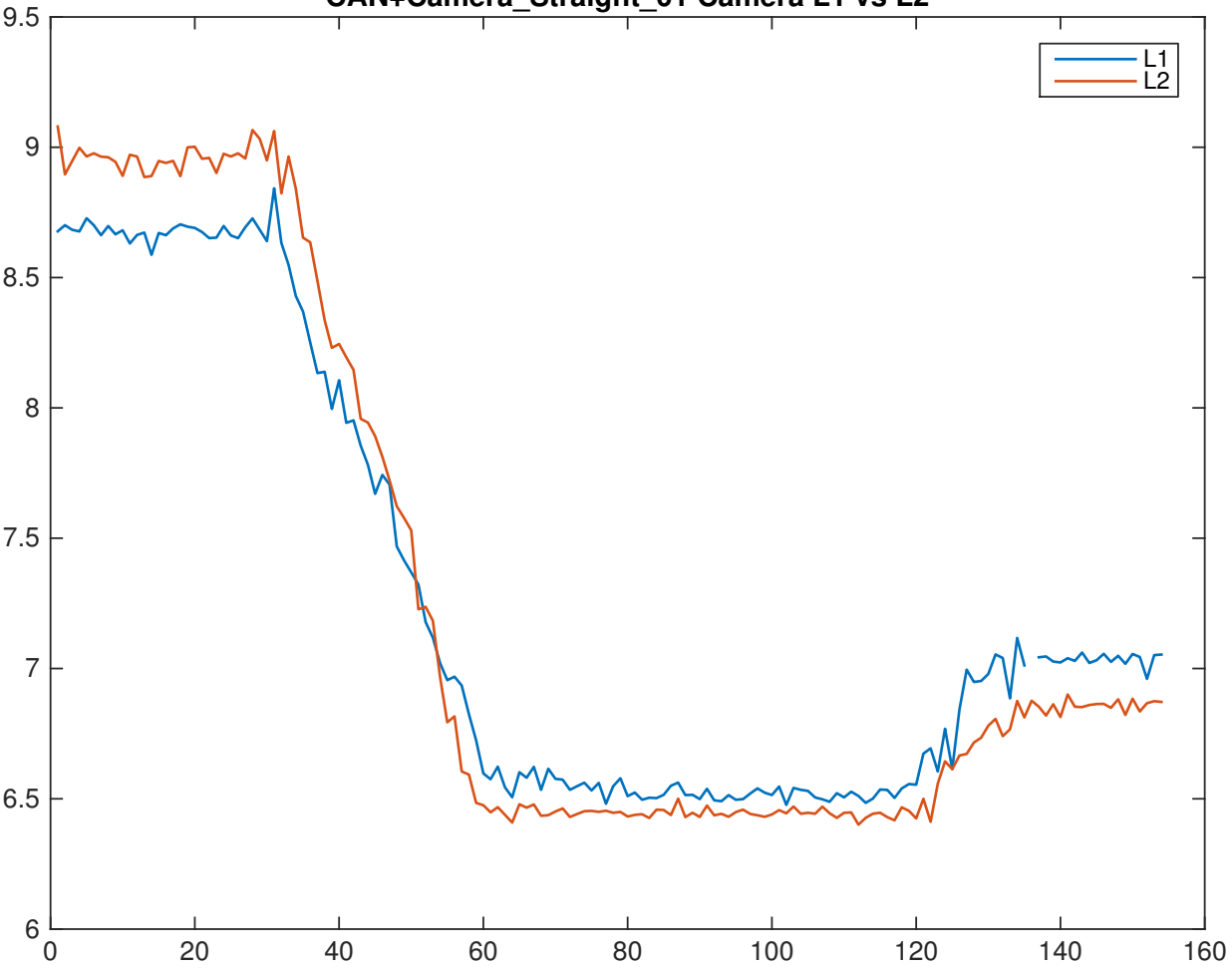


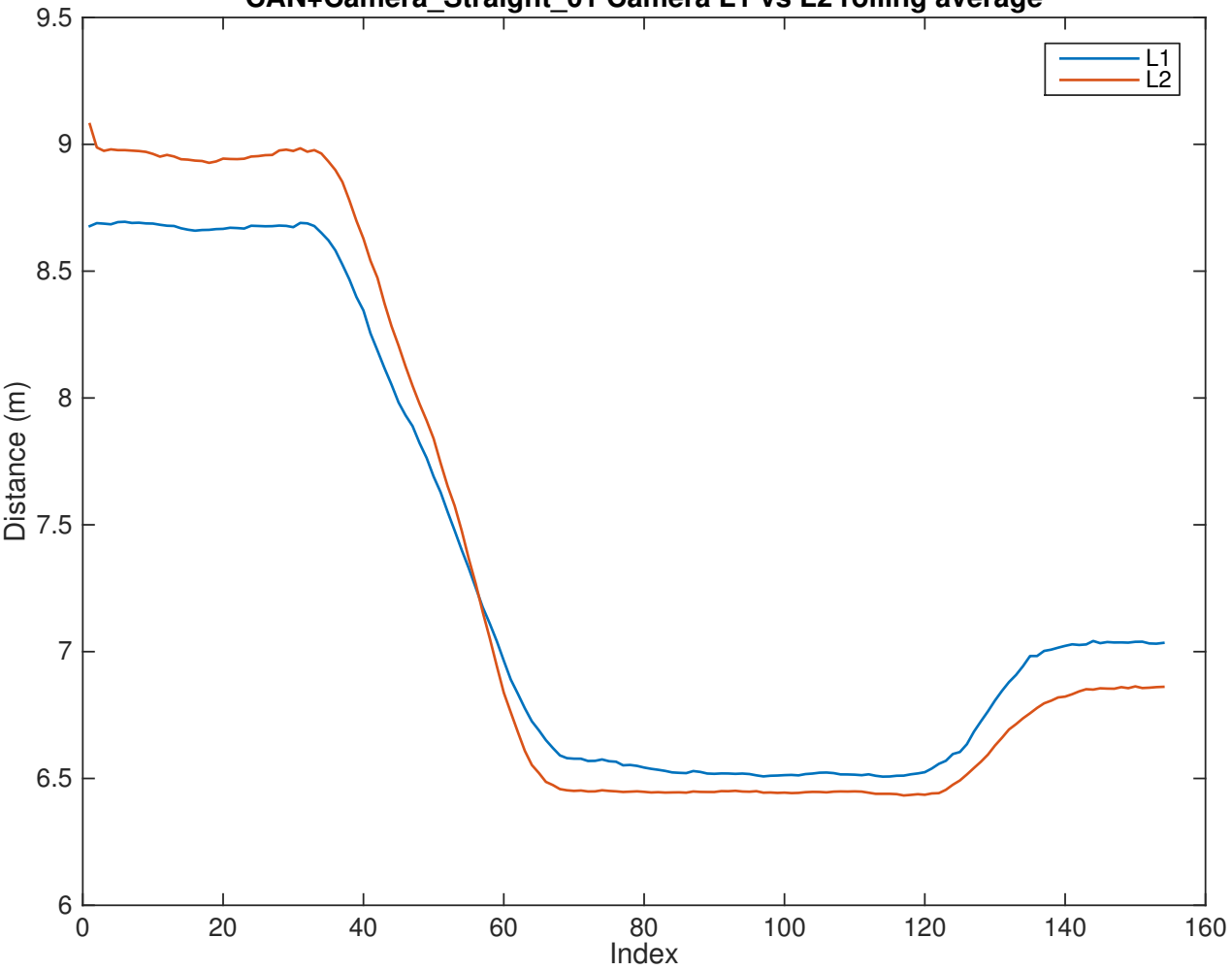
CAN+Camera\_Straight\_01 Initial Path



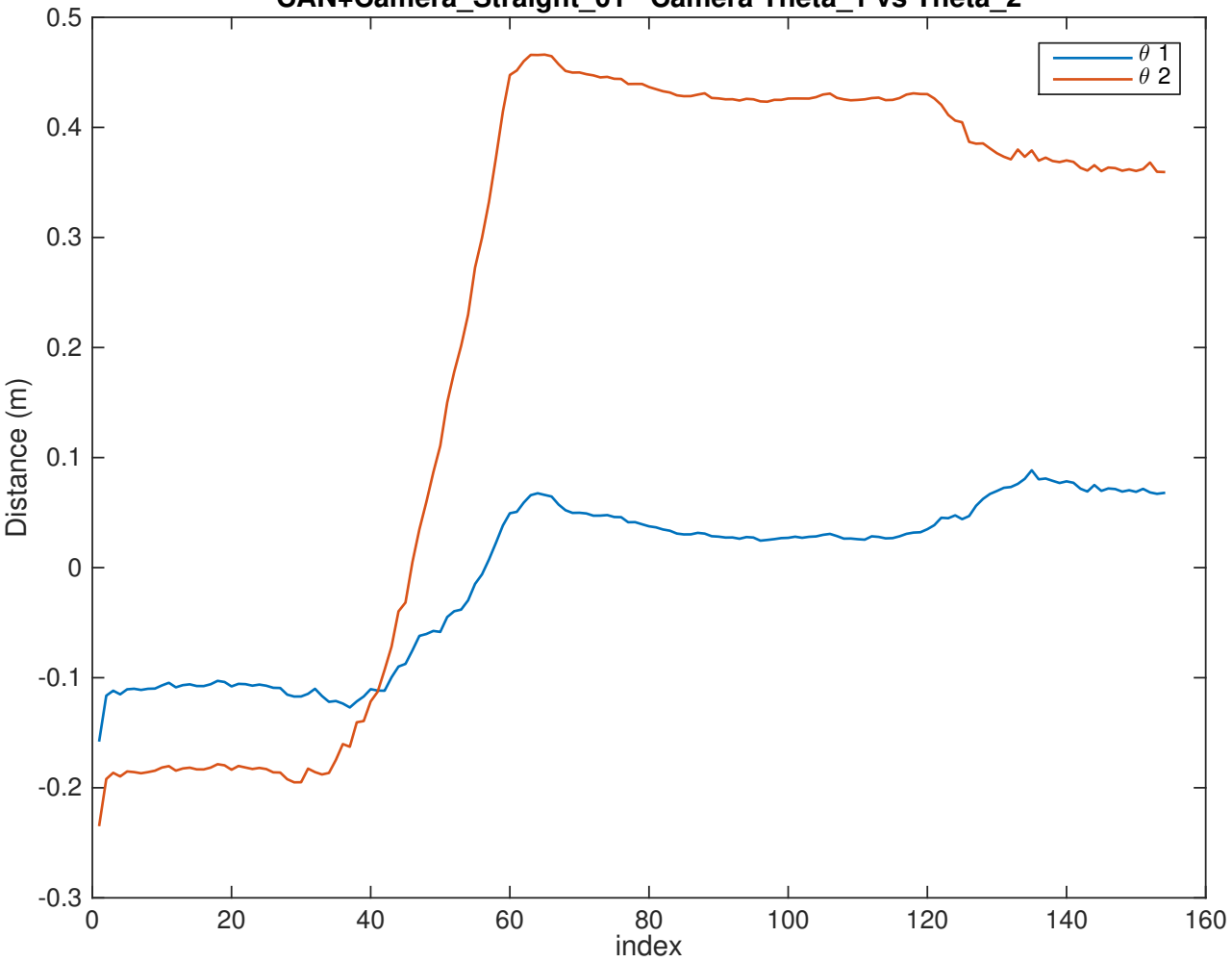
CAN+Camera\_Straight\_01 Camera L1 vs L2



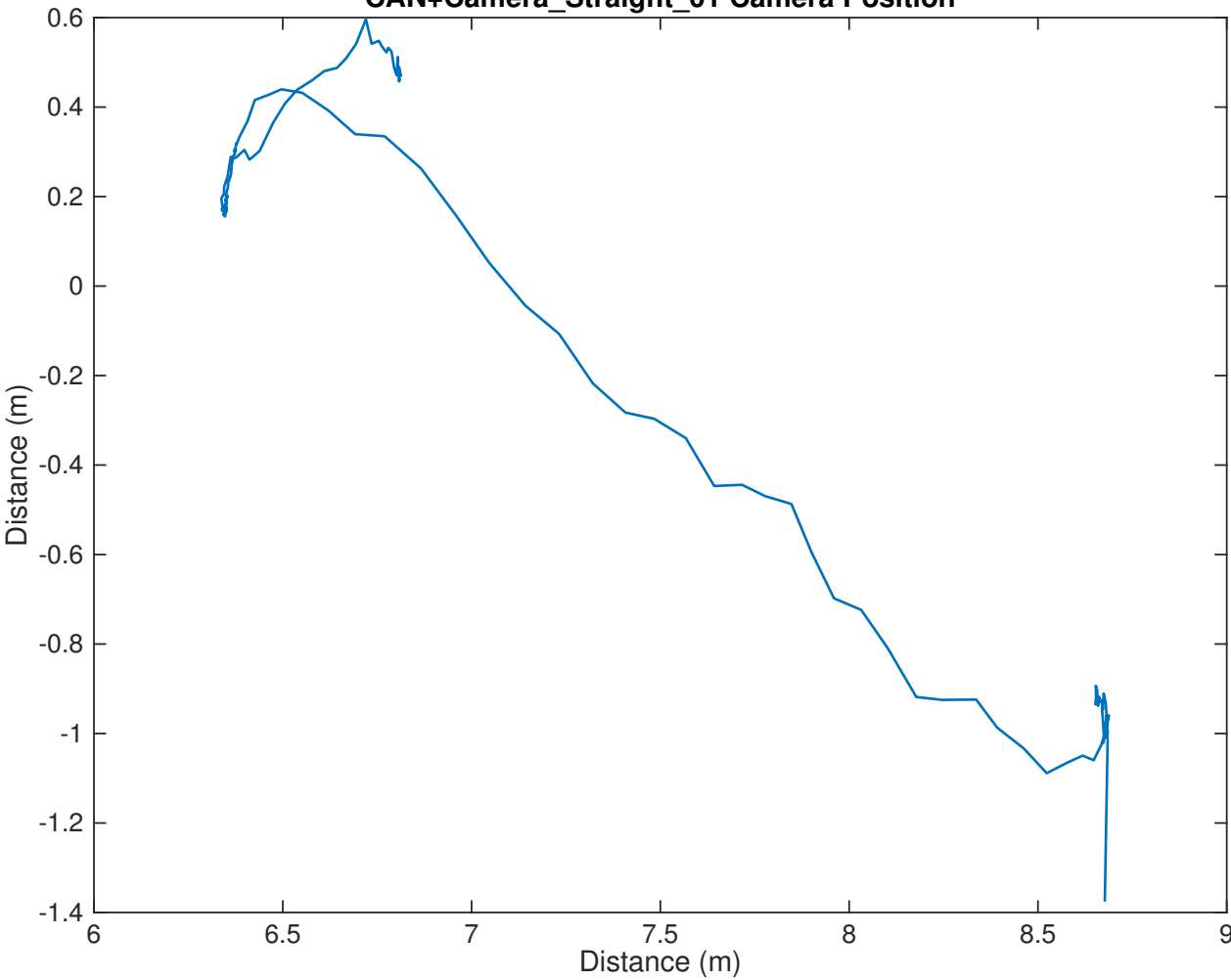
CAN+Camera\_Straight\_01 Camera L1 vs L2 rolling average



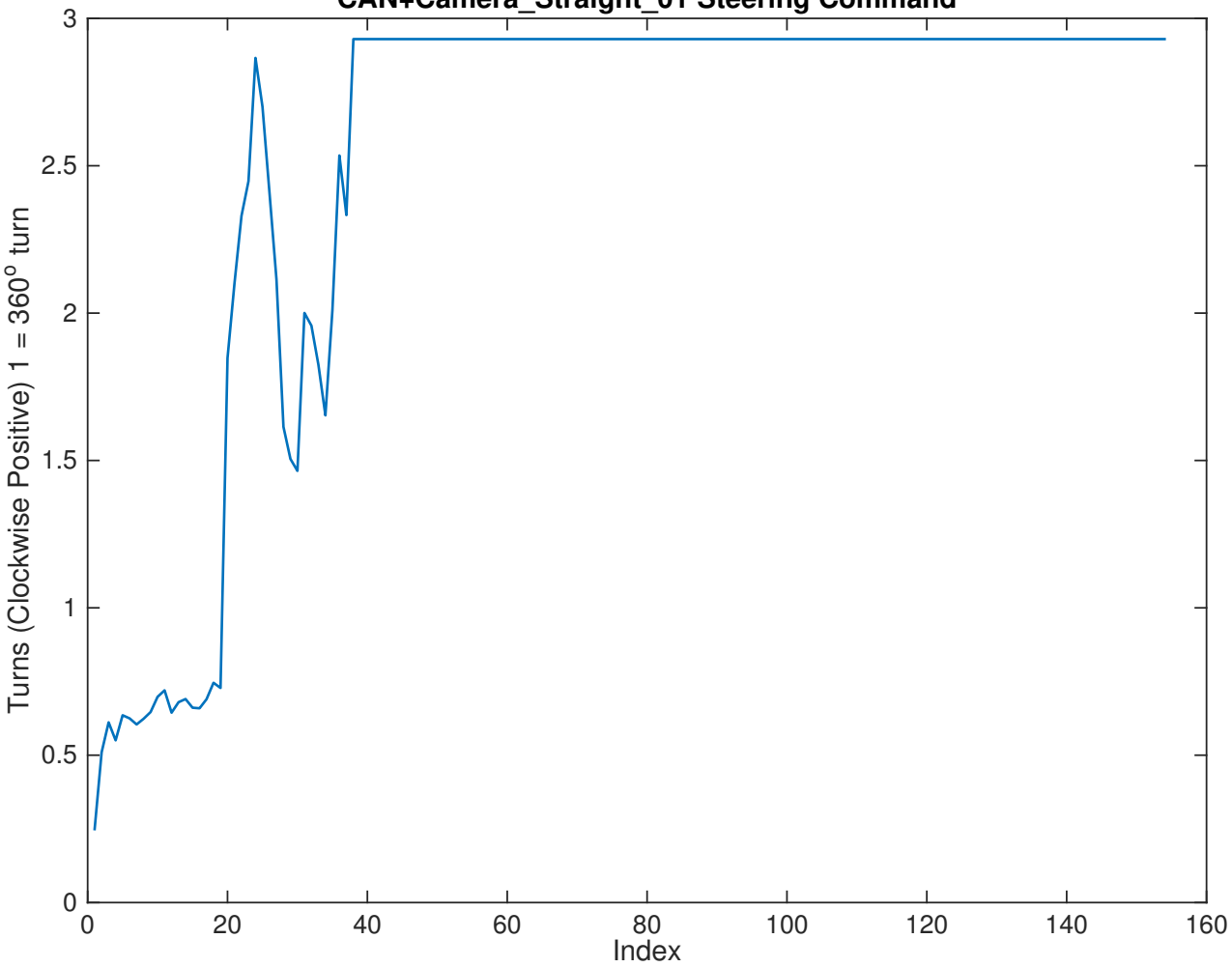
CAN+Camera\_Straight\_01 Camera Theta\_1 vs Theta\_2



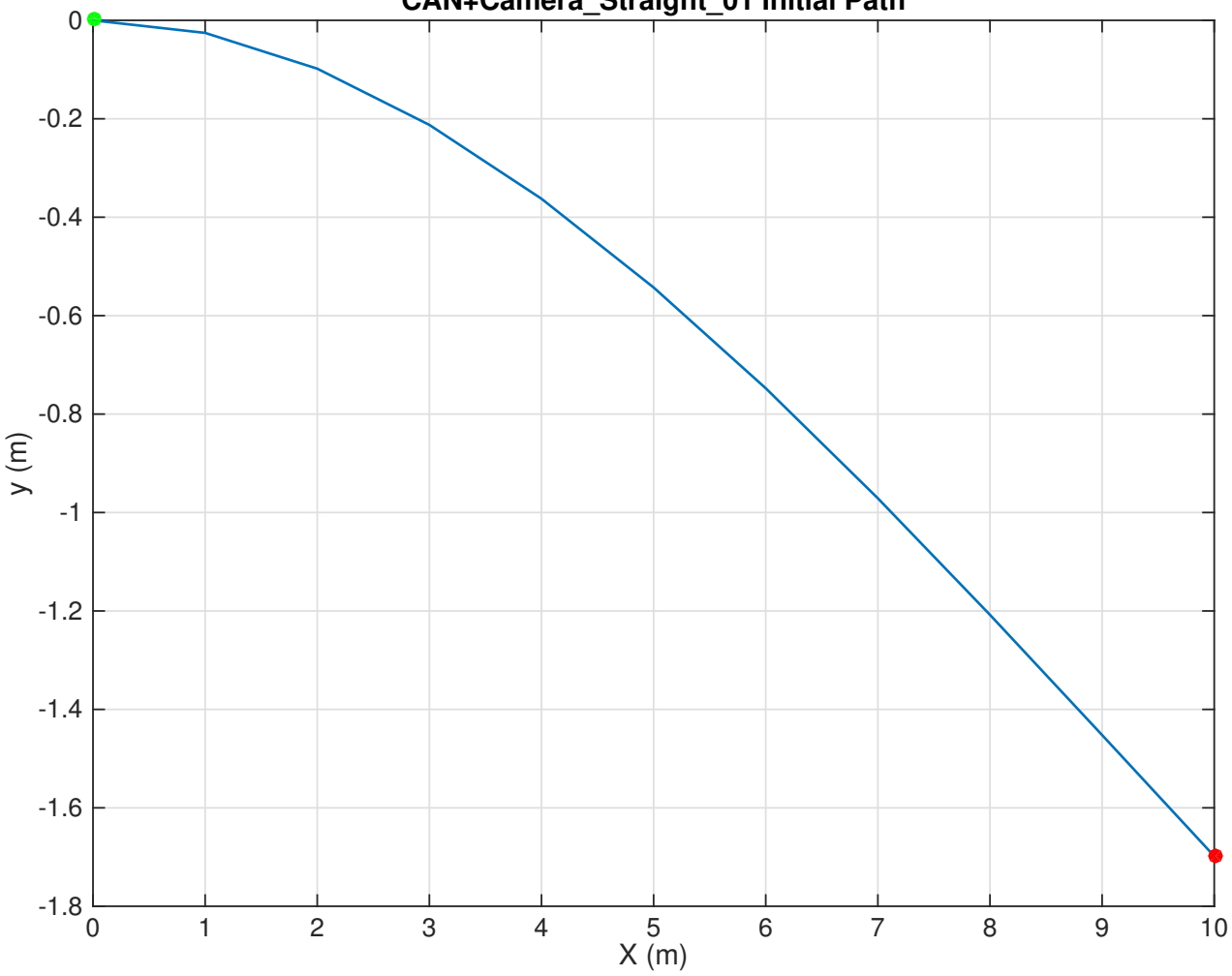
CAN+Camera\_Straight\_01 Camera Position



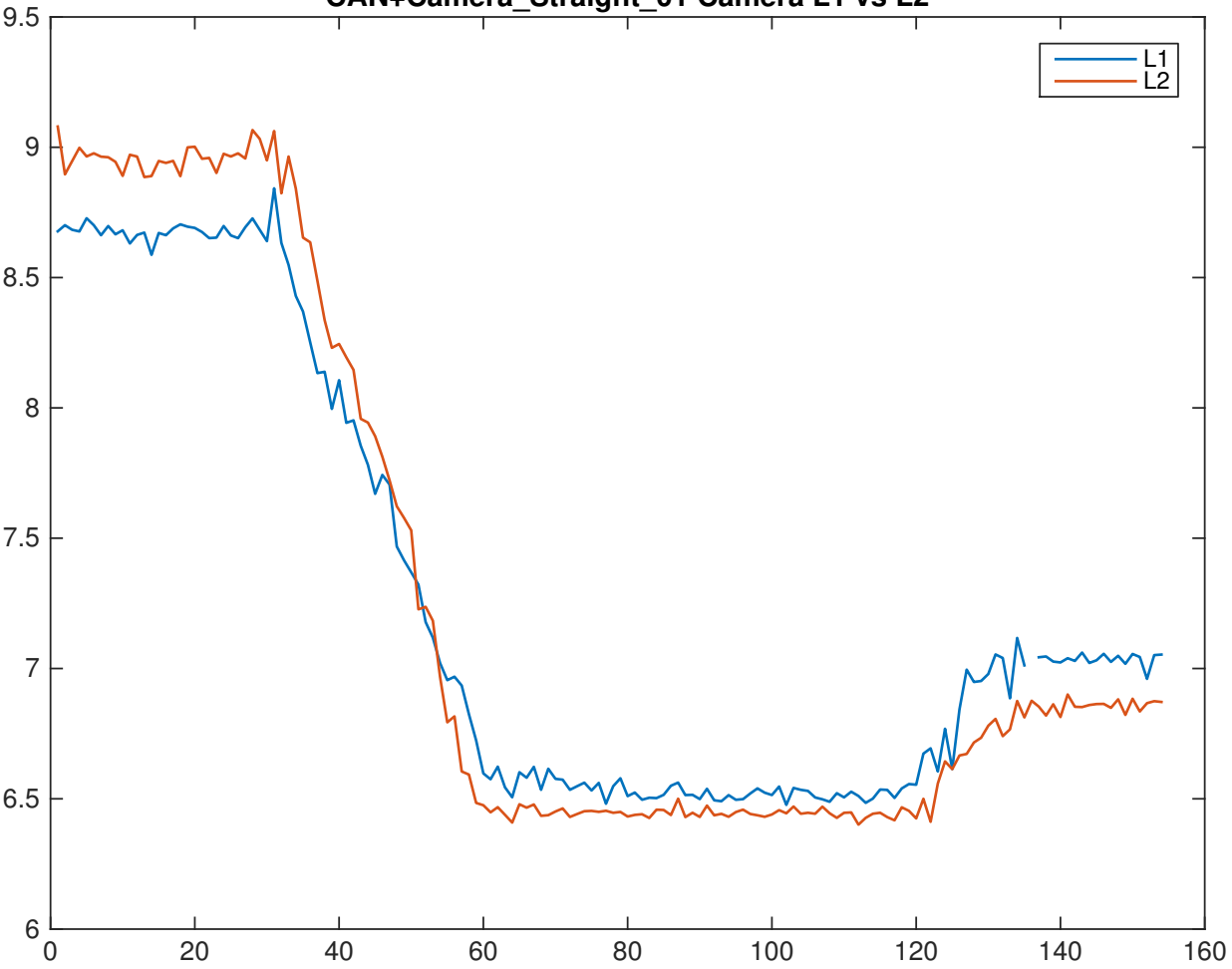
CAN+Camera\_Straight\_01 Steering Command



CAN+Camera\_Straight\_01 Initial Path

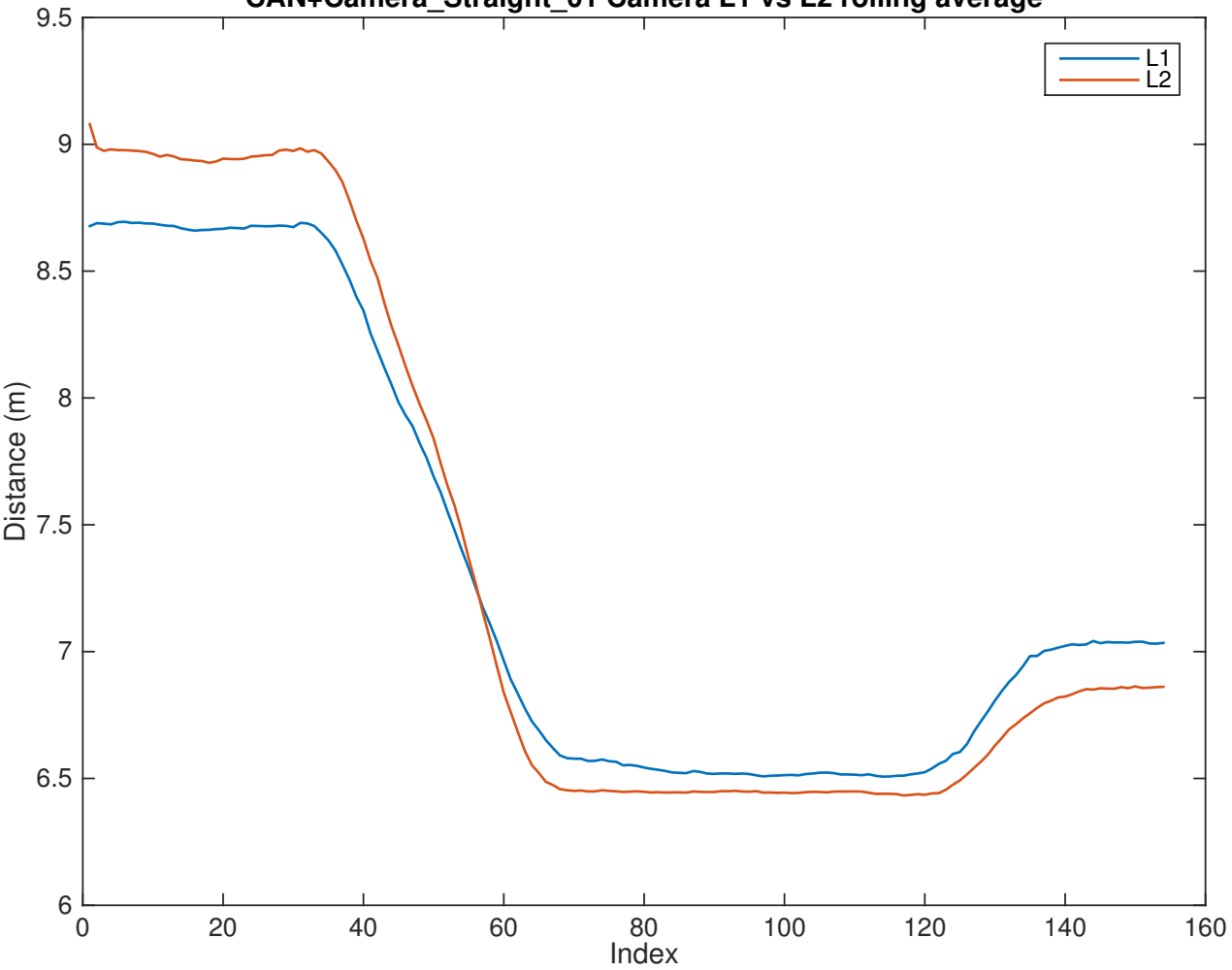


CAN+Camera\_Straight\_01 Camera L1 vs L2

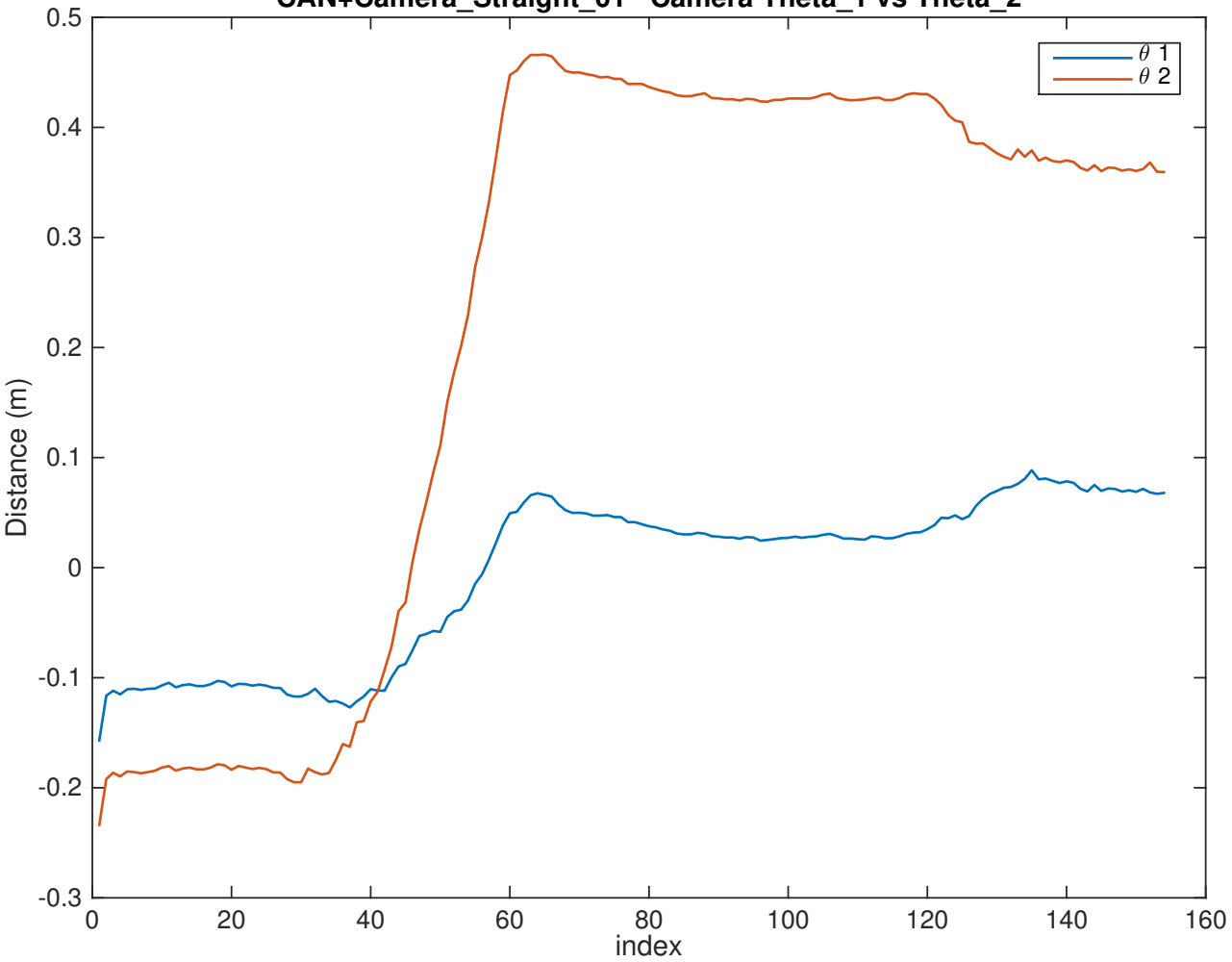




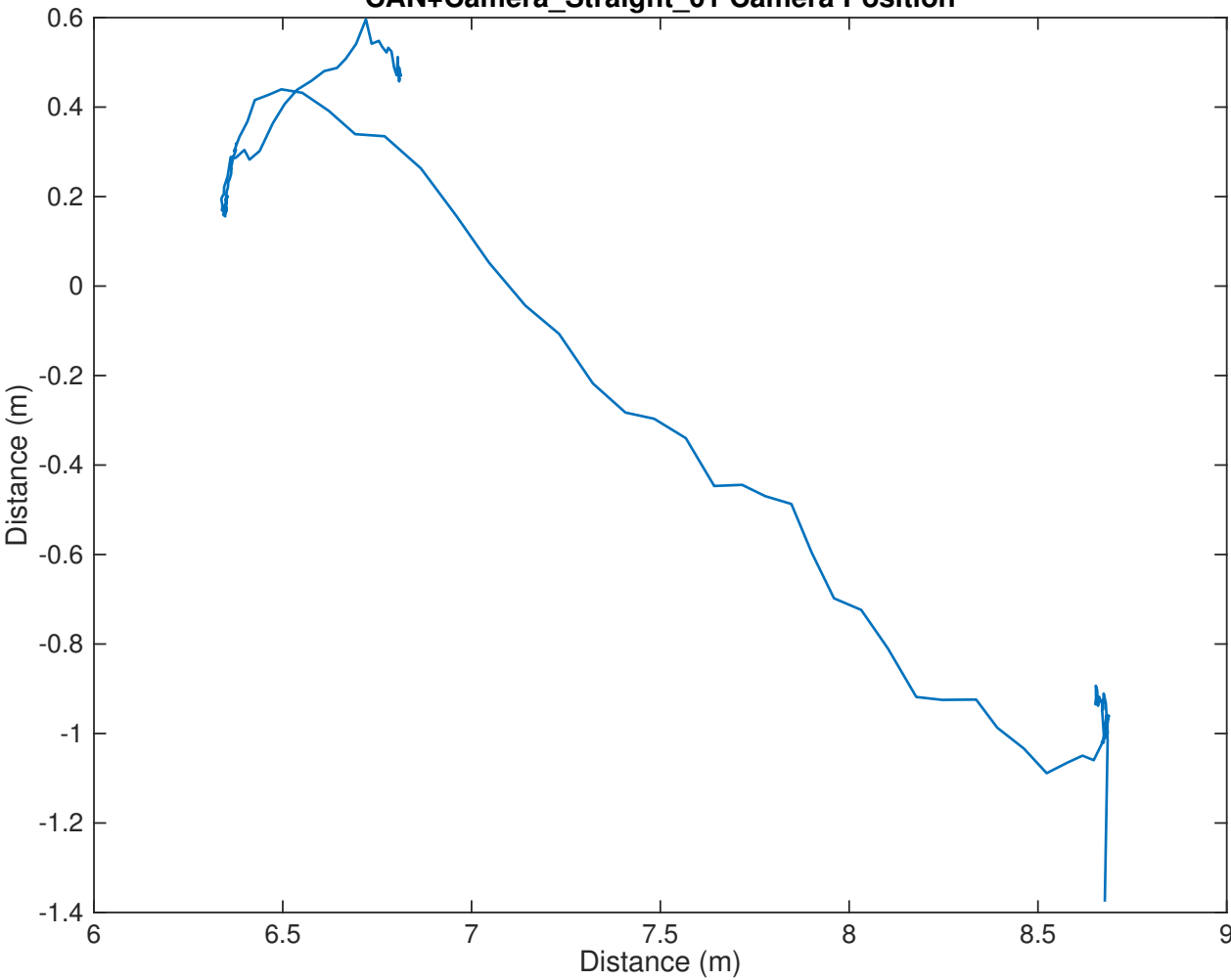
CAN+Camera\_Straight\_01 Camera L1 vs L2 rolling average



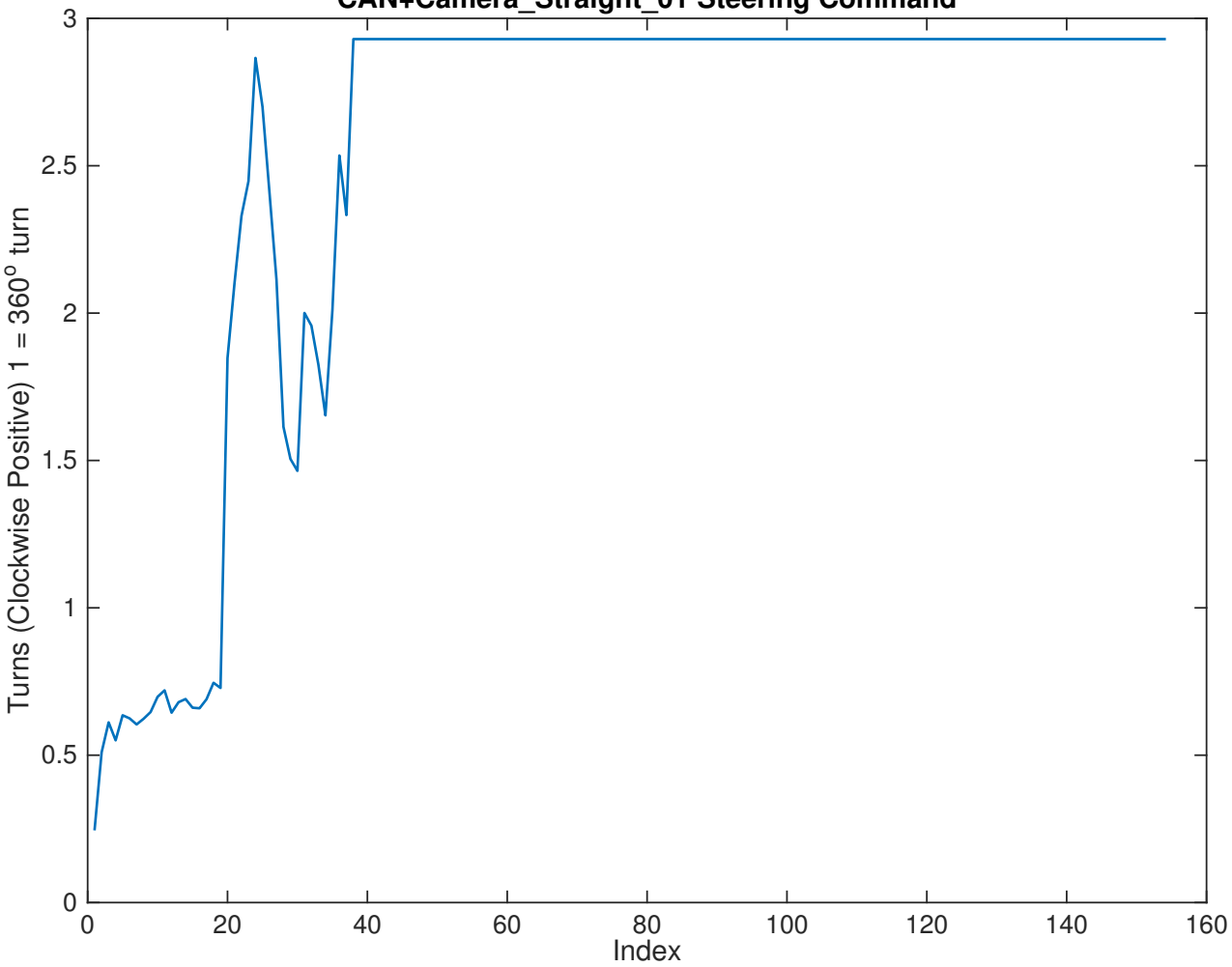
CAN+Camera\_Straight\_01 Camera Theta\_1 vs Theta\_2



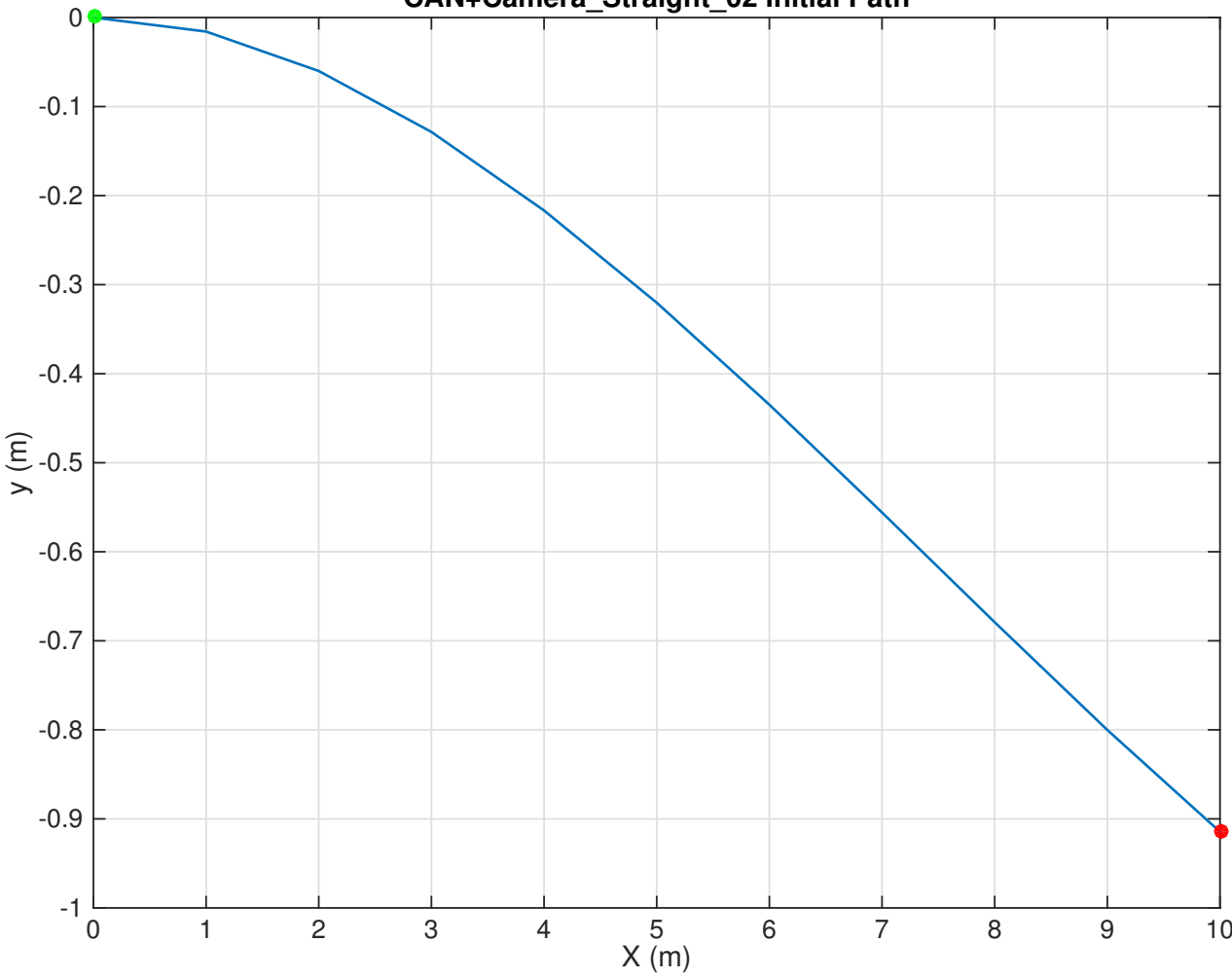
CAN+Camera\_Straight\_01 Camera Position



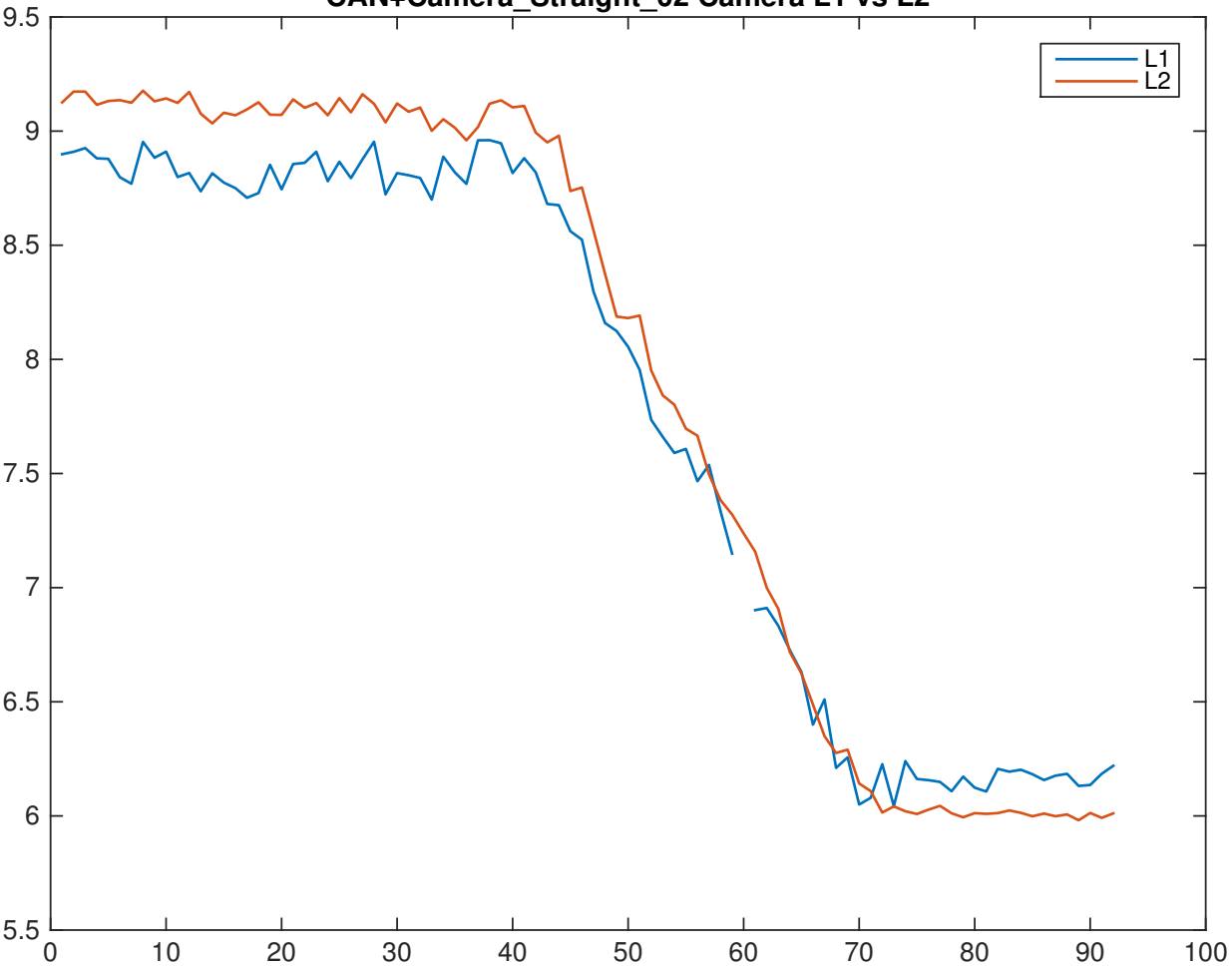
CAN+Camera\_Straight\_01 Steering Command



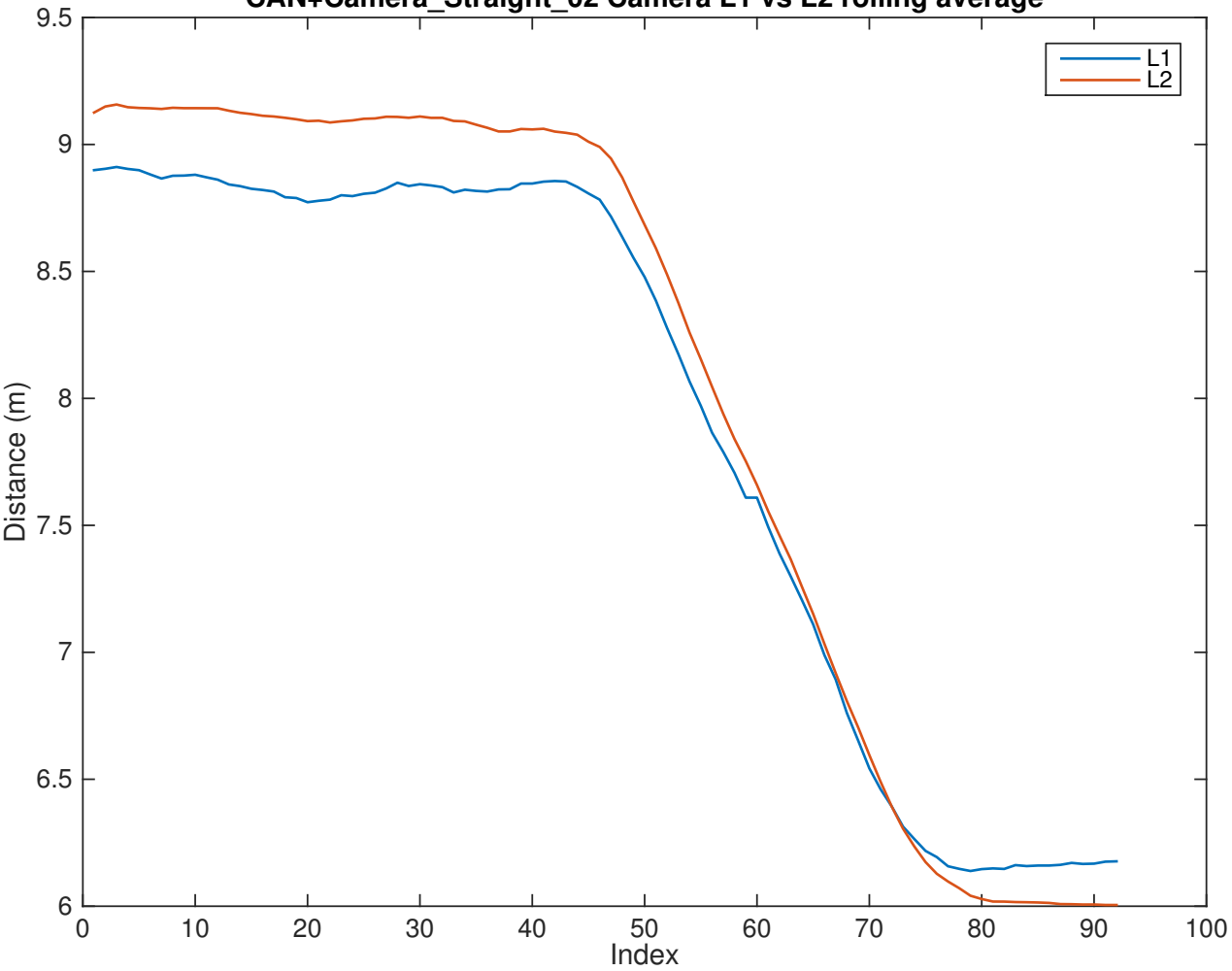
CAN+Camera\_Straight\_02 Initial Path



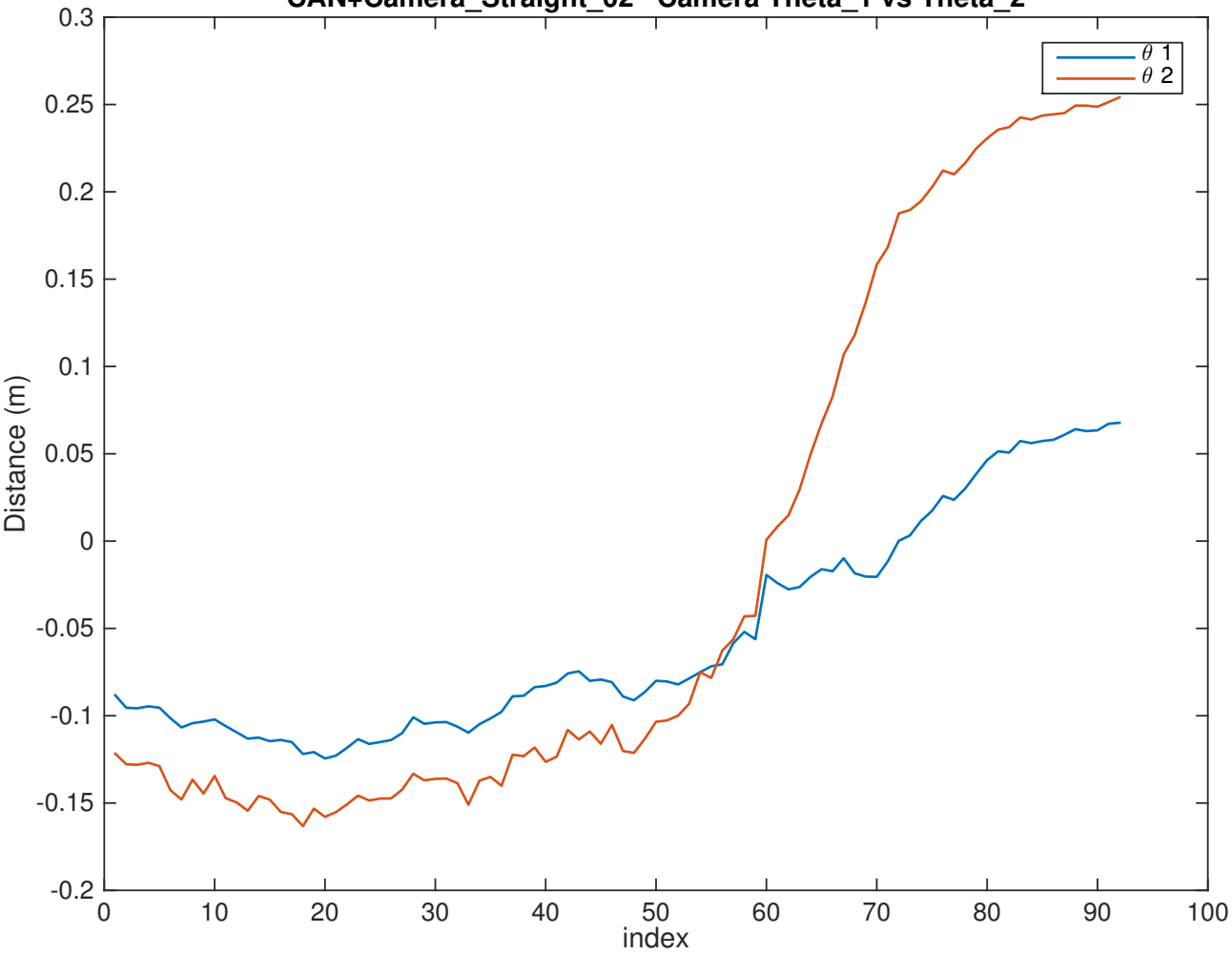
CAN+Camera\_Straight\_02 Camera L1 vs L2



CAN+Camera\_Straight\_02 Camera L1 vs L2 rolling average

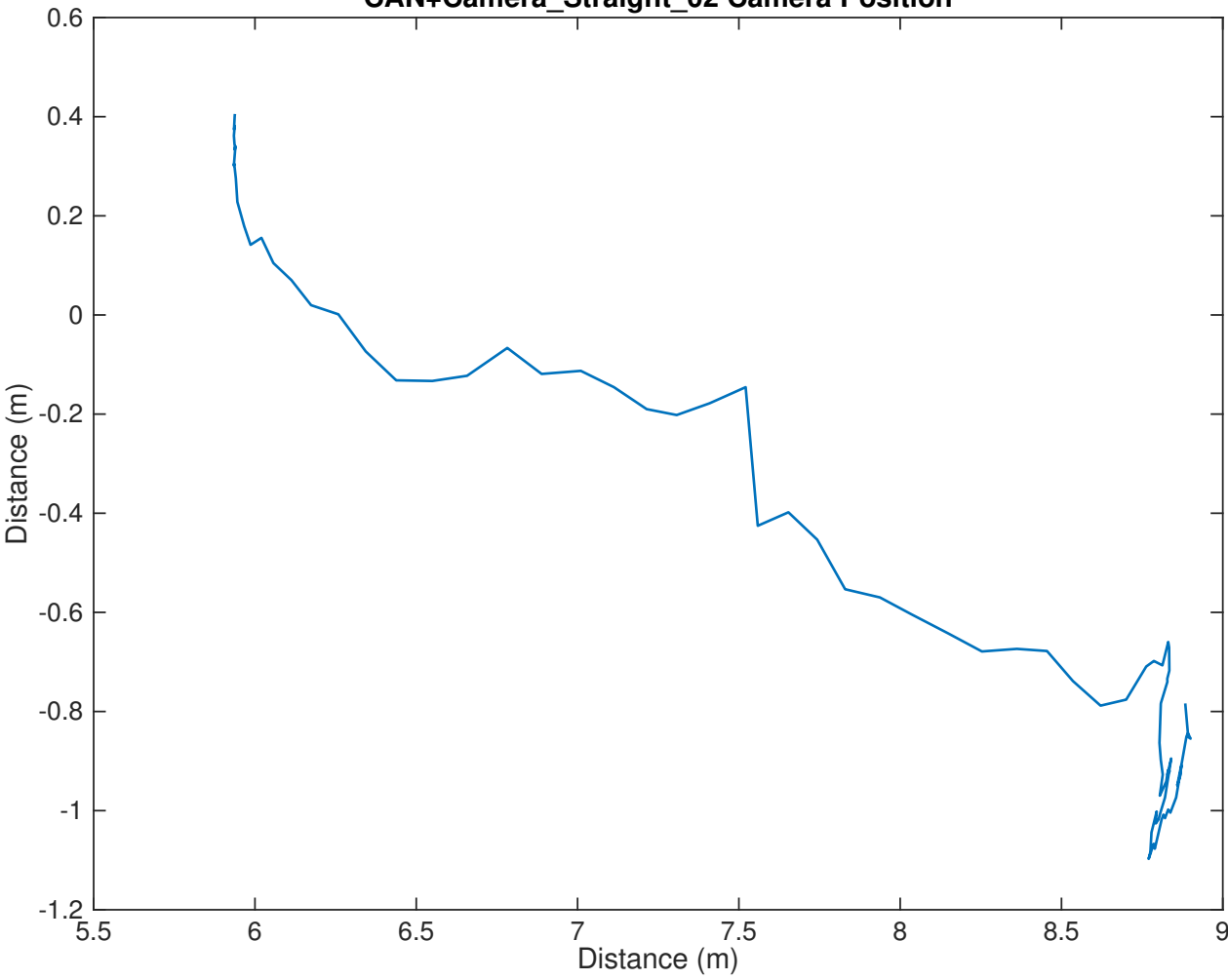


CAN+Camera\_Straight\_02 Camera Theta\_1 vs Theta\_2





CAN+Camera\_Straight\_02 Camera Position



CAN+Camera\_Straight\_02 Steering Command

