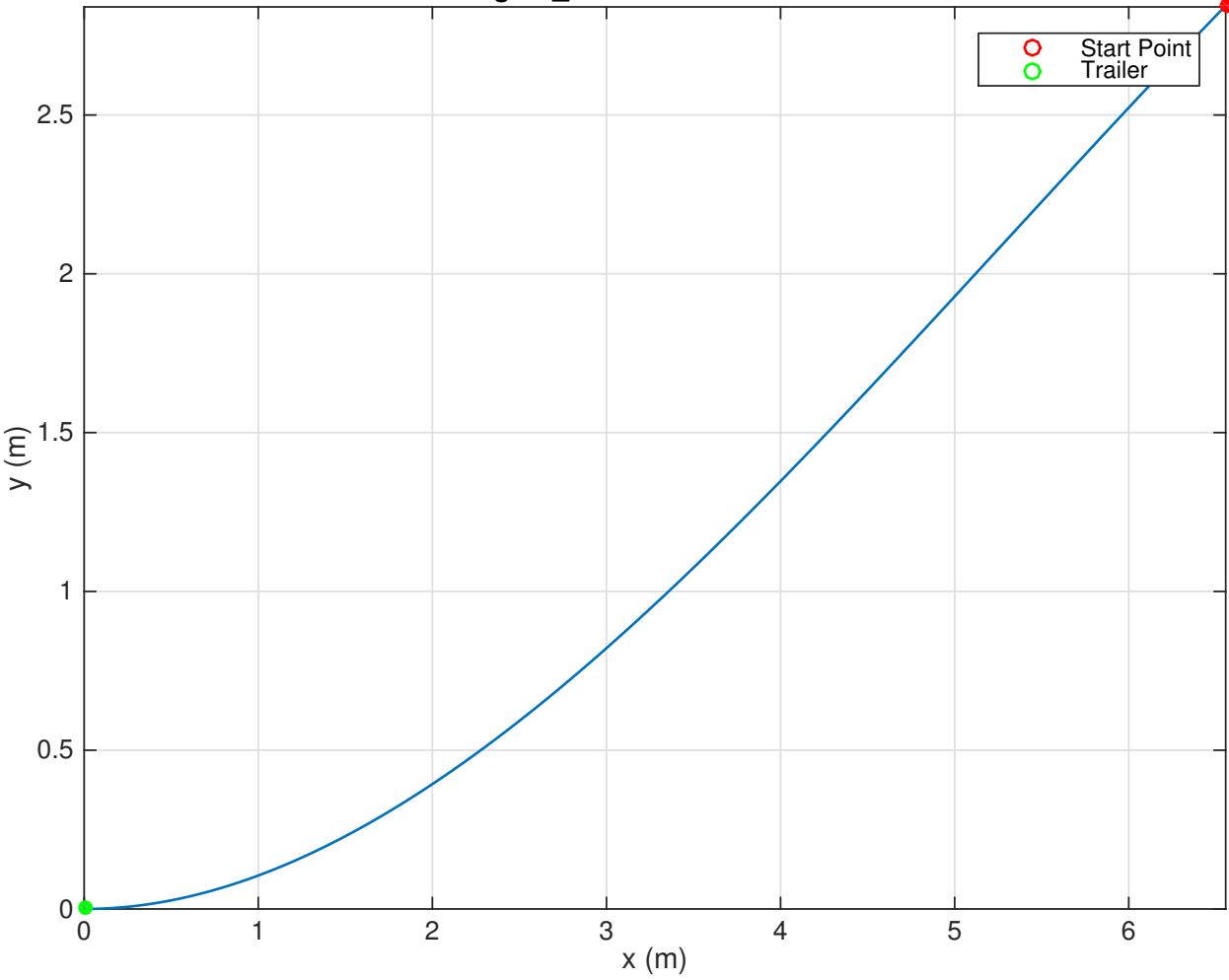


Angled_initialPath1 All Paths



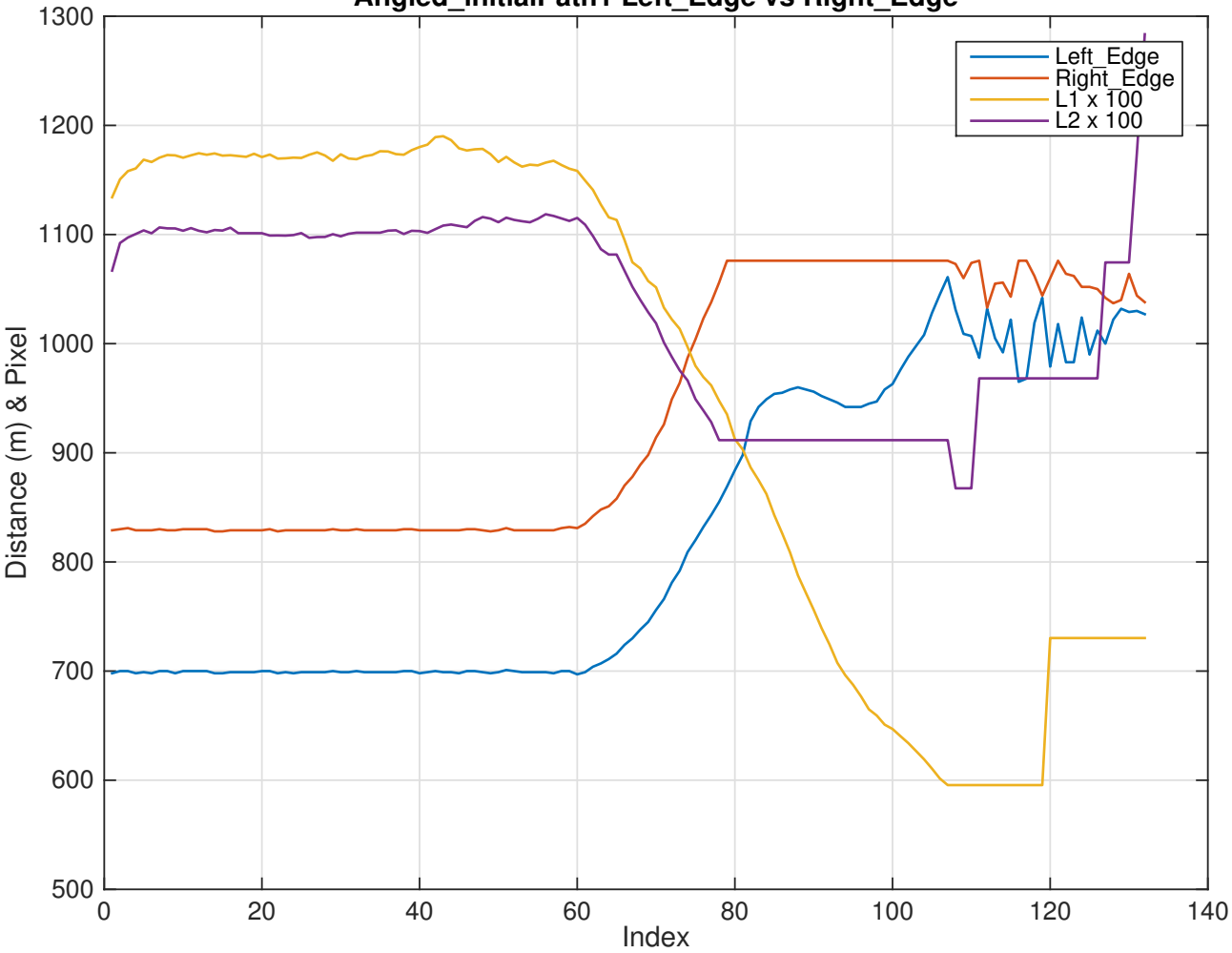
Number_Of_Unique_Paths

King_Pin_Detected

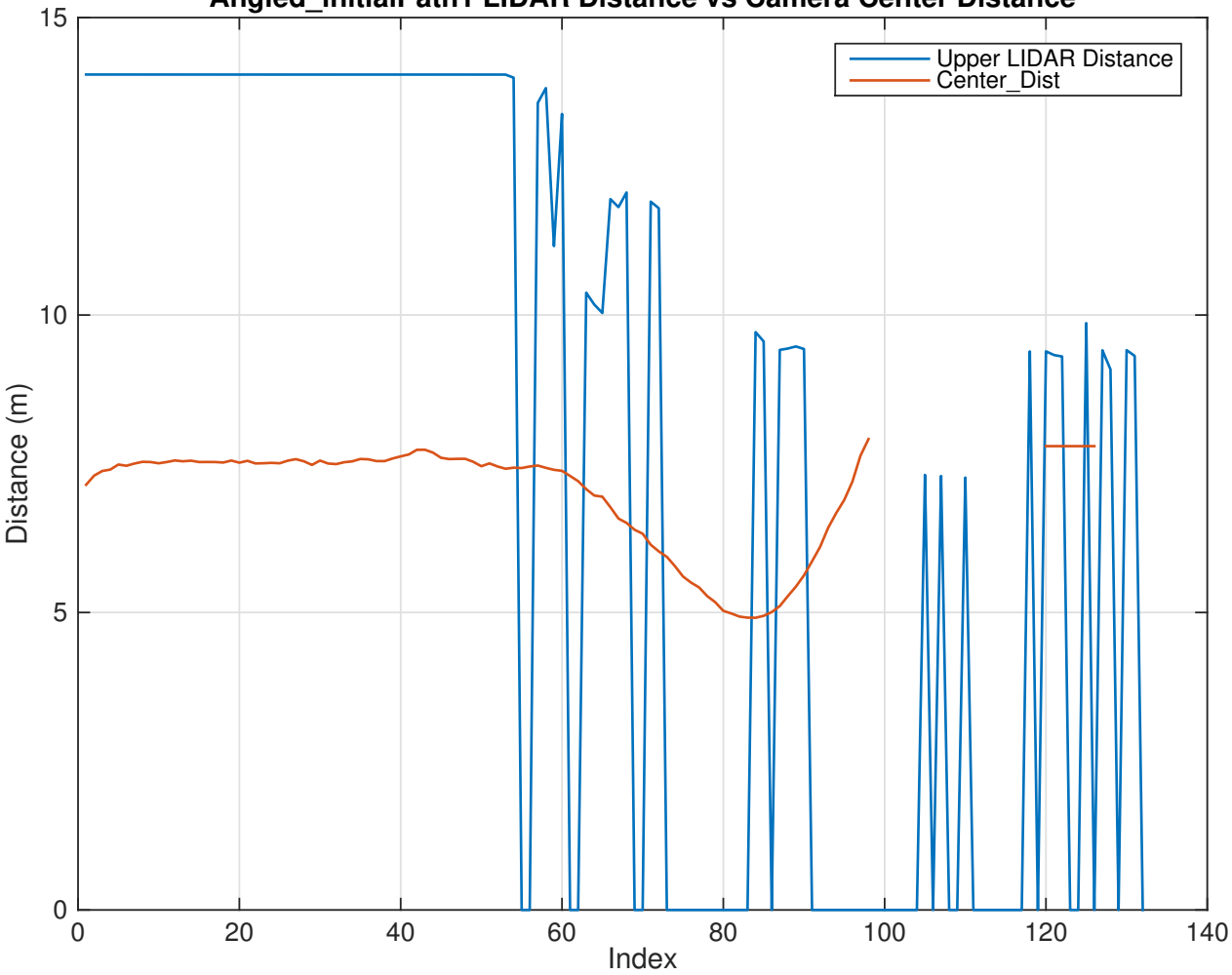
1

false

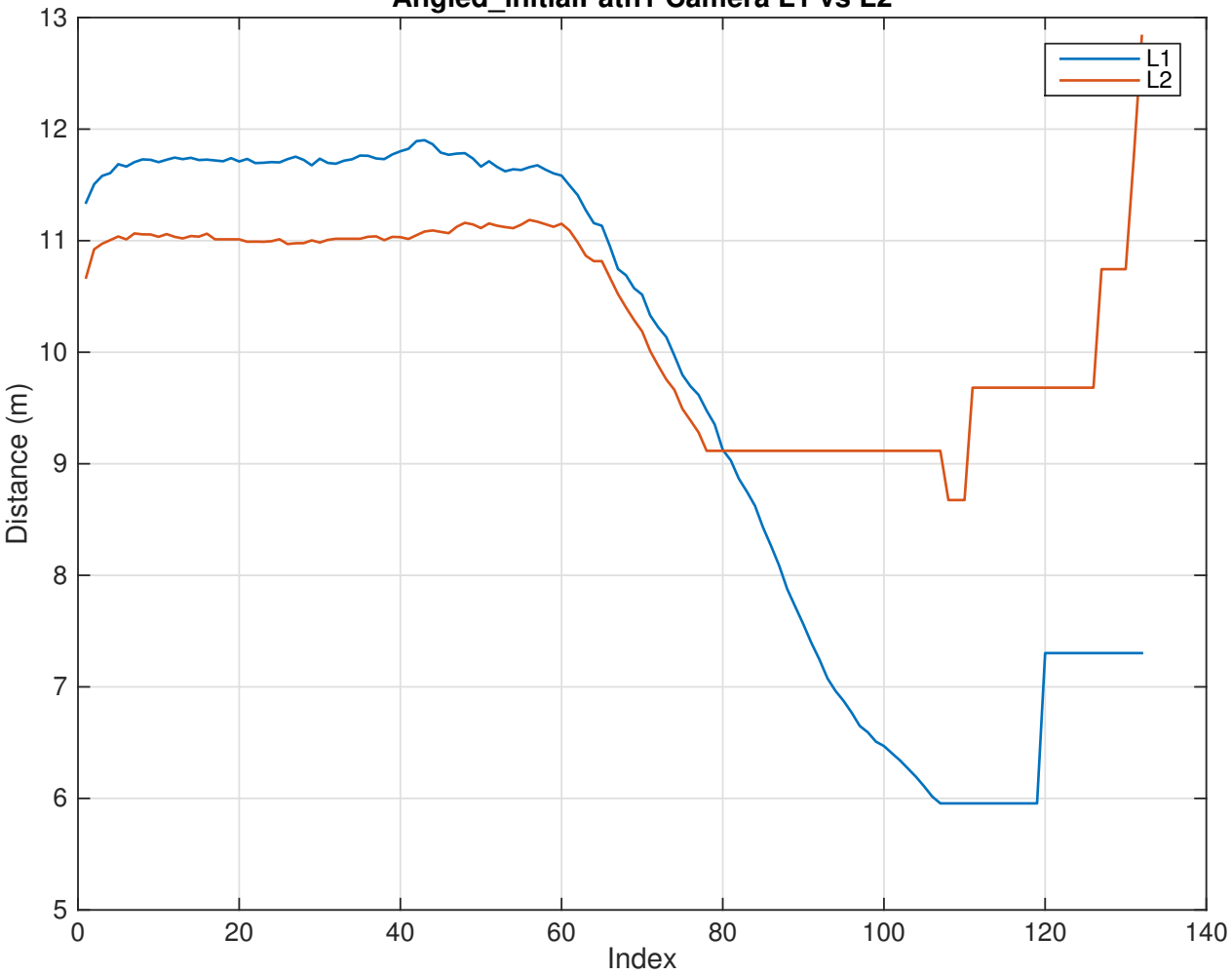
Angled_initialPath1 Left_Edge vs Right_Edge



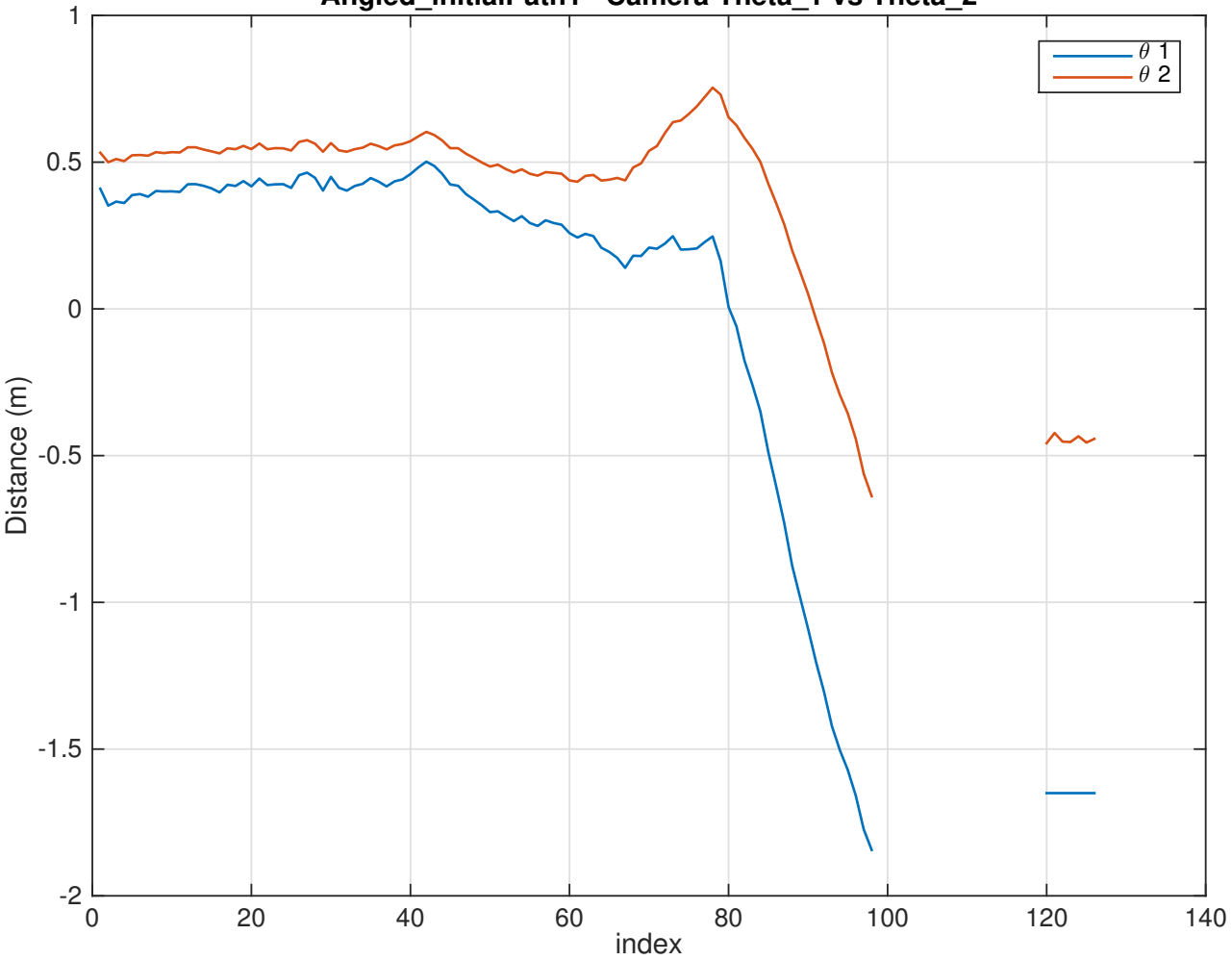
Angled_initialPath1 LIDAR Distance vs Camera Center Distance



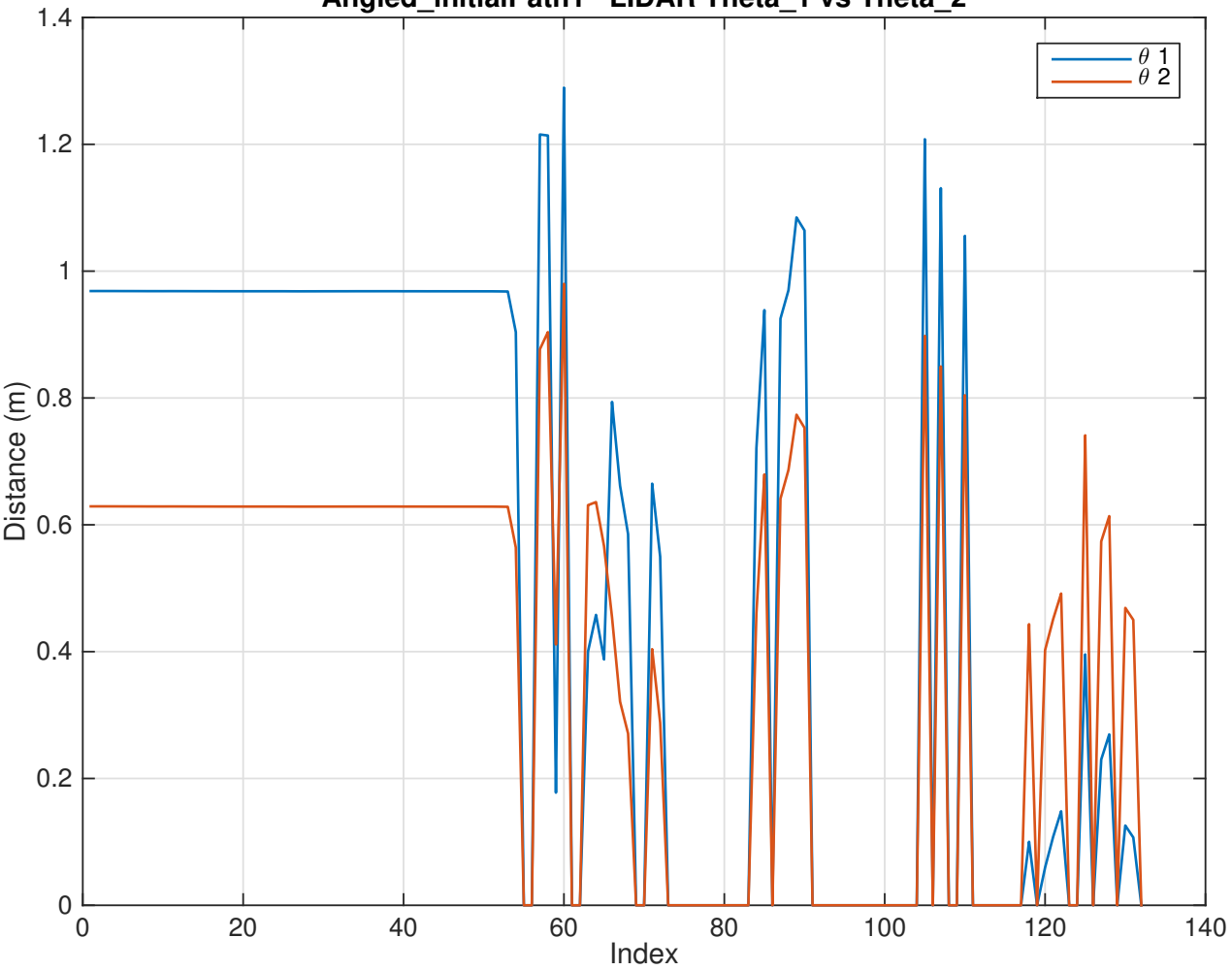
Angled_initialPath1 Camera L1 vs L2



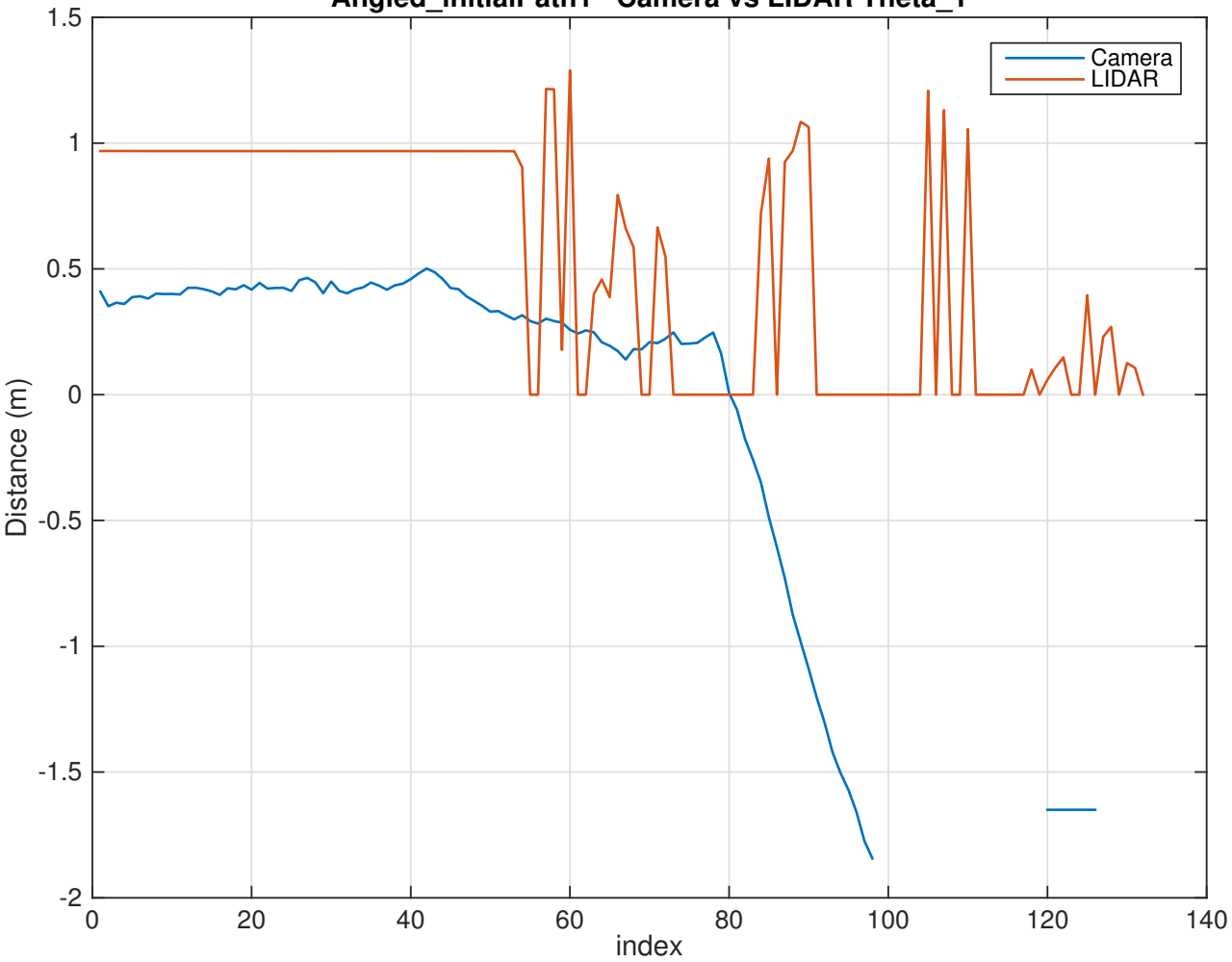
Angled_initialPath1 Camera Theta_1 vs Theta_2



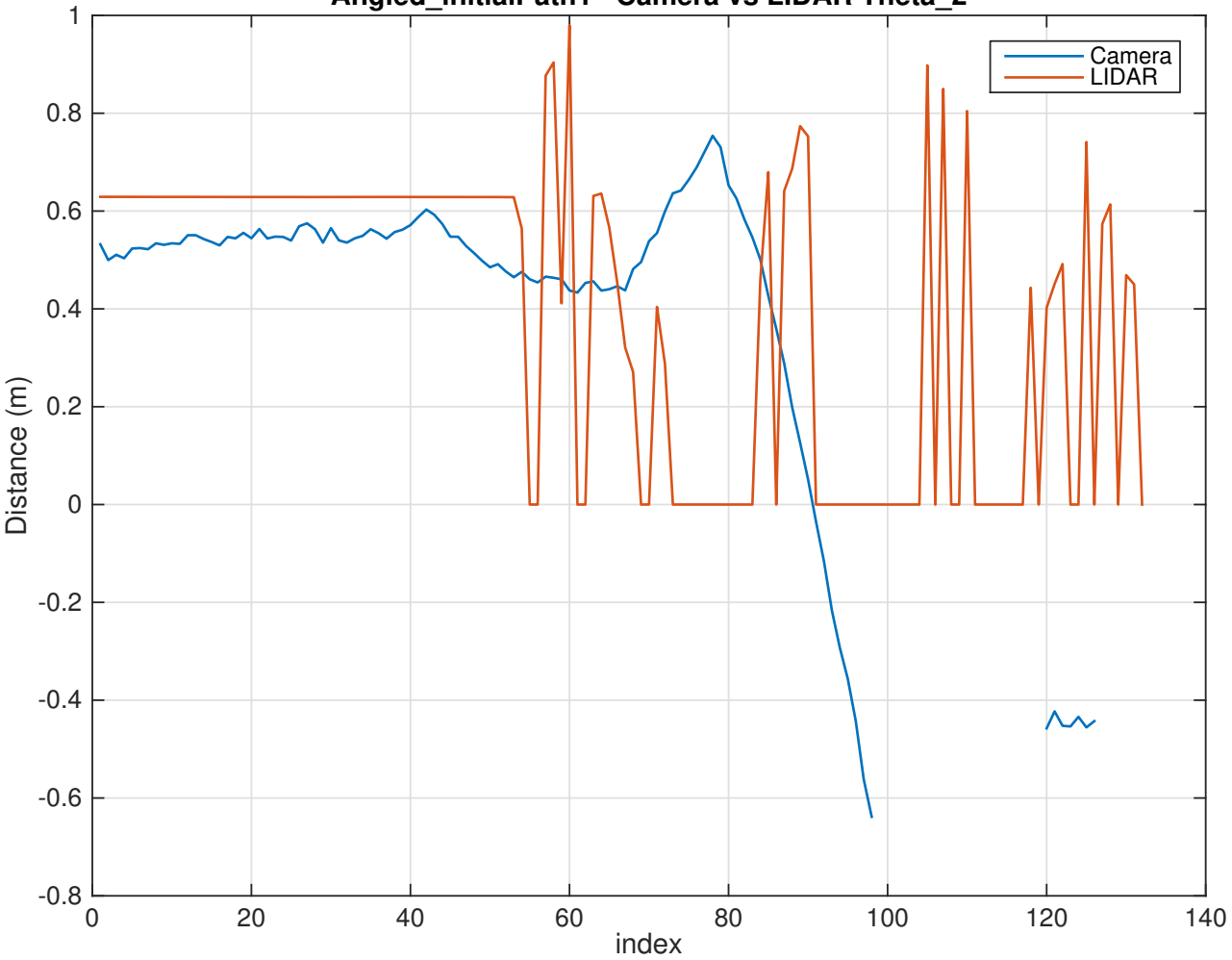
Angled_initialPath1 LIDAR Theta_1 vs Theta_2



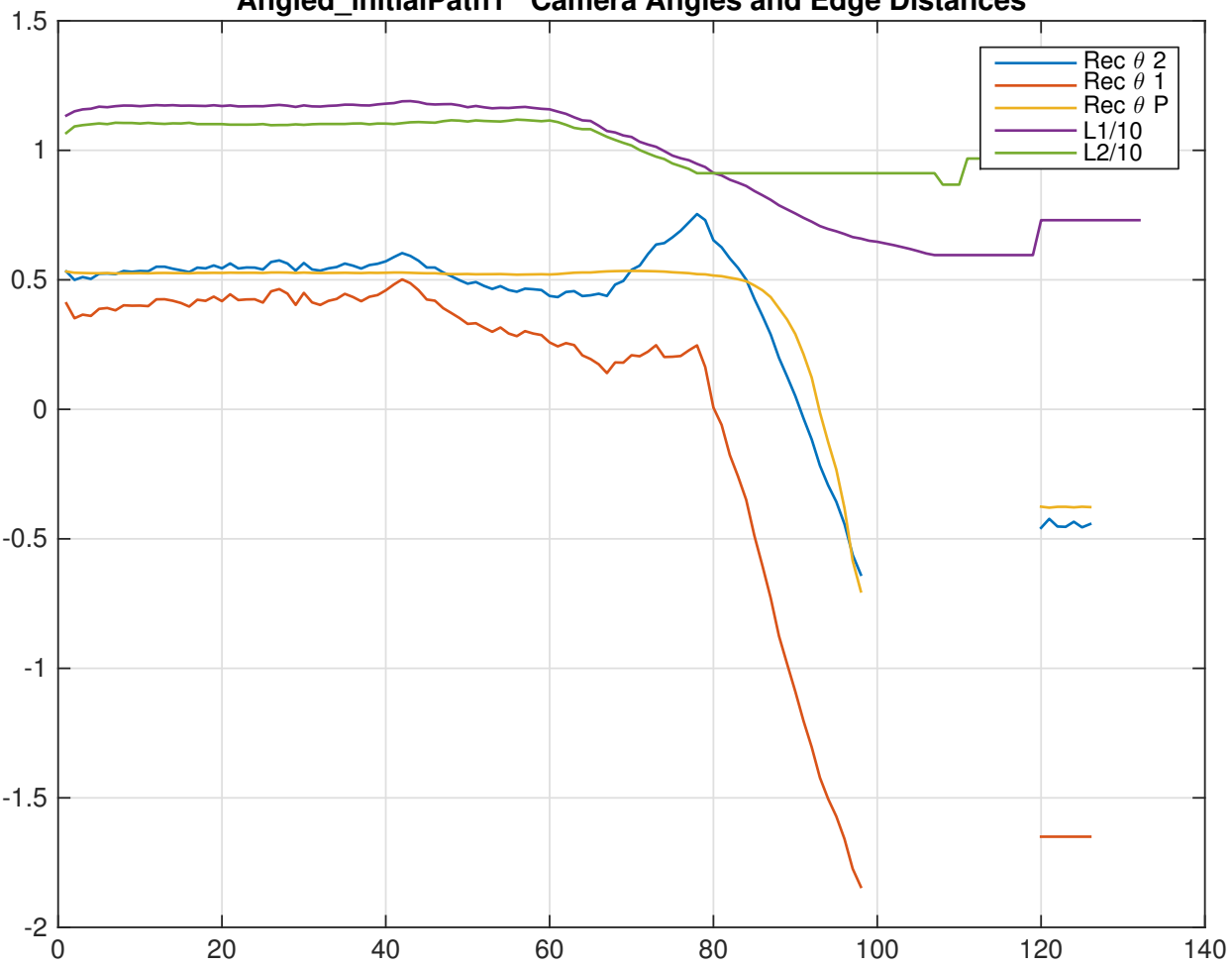
Angled_initialPath1 Camera vs LIDAR Theta_1



Angled_initialPath1 Camera vs LIDAR Theta_2



Angled_initialPath1 Camera Angles and Edge Distances



Angled_initialPath1 Calculated vs. Actual Steering

