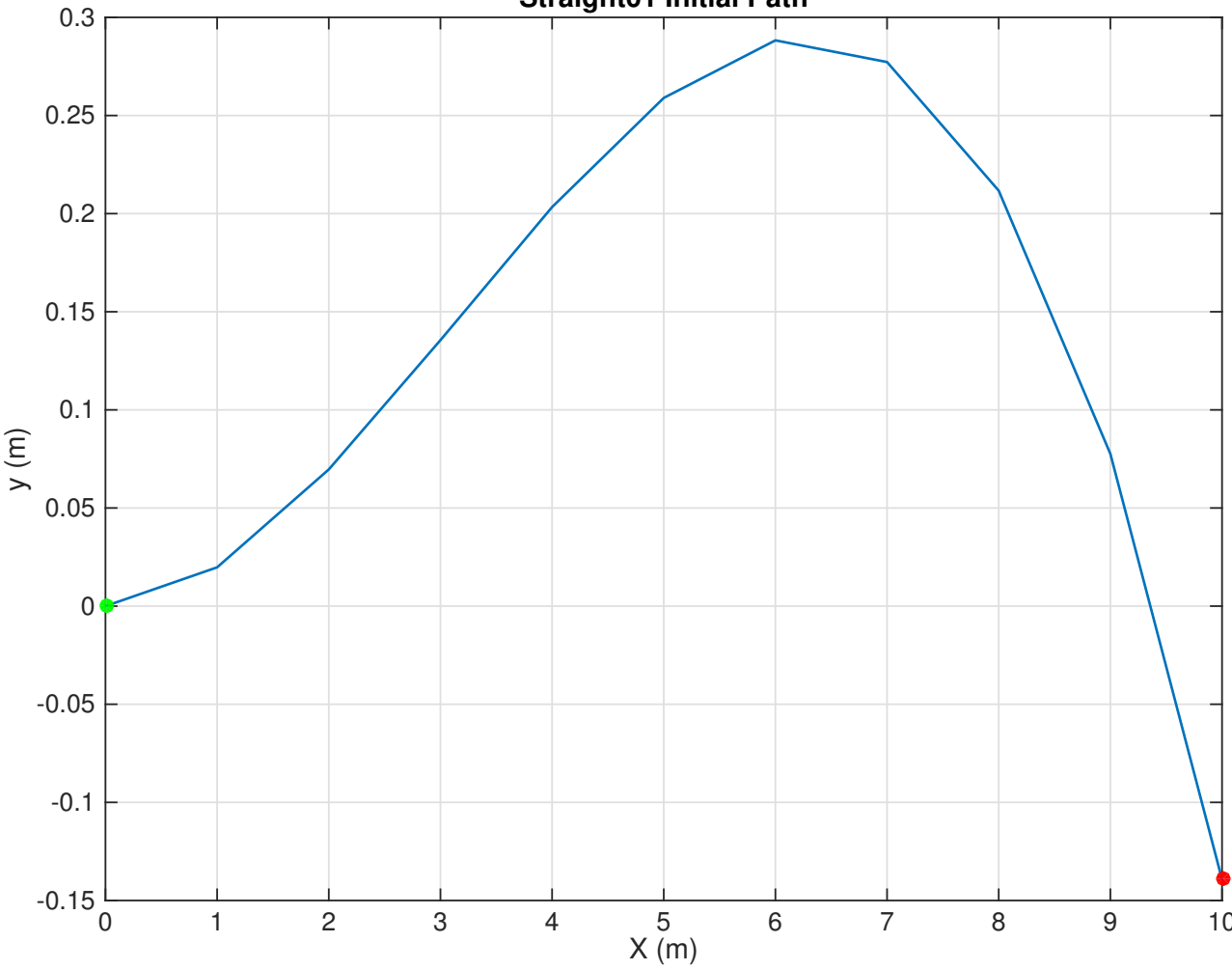


Straight01 Initial Path



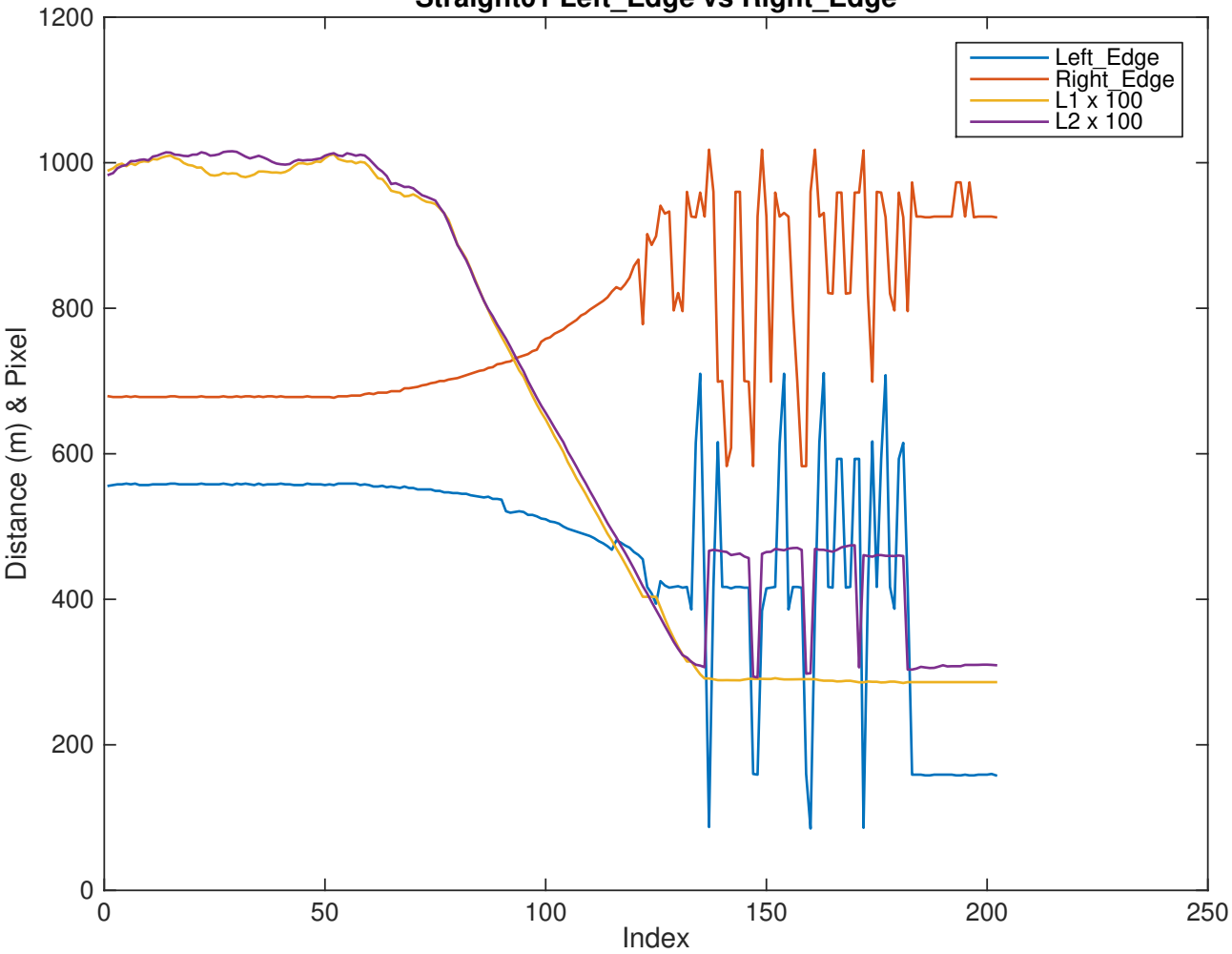
Number_Of_Unique_Paths

King_Pin_Detected

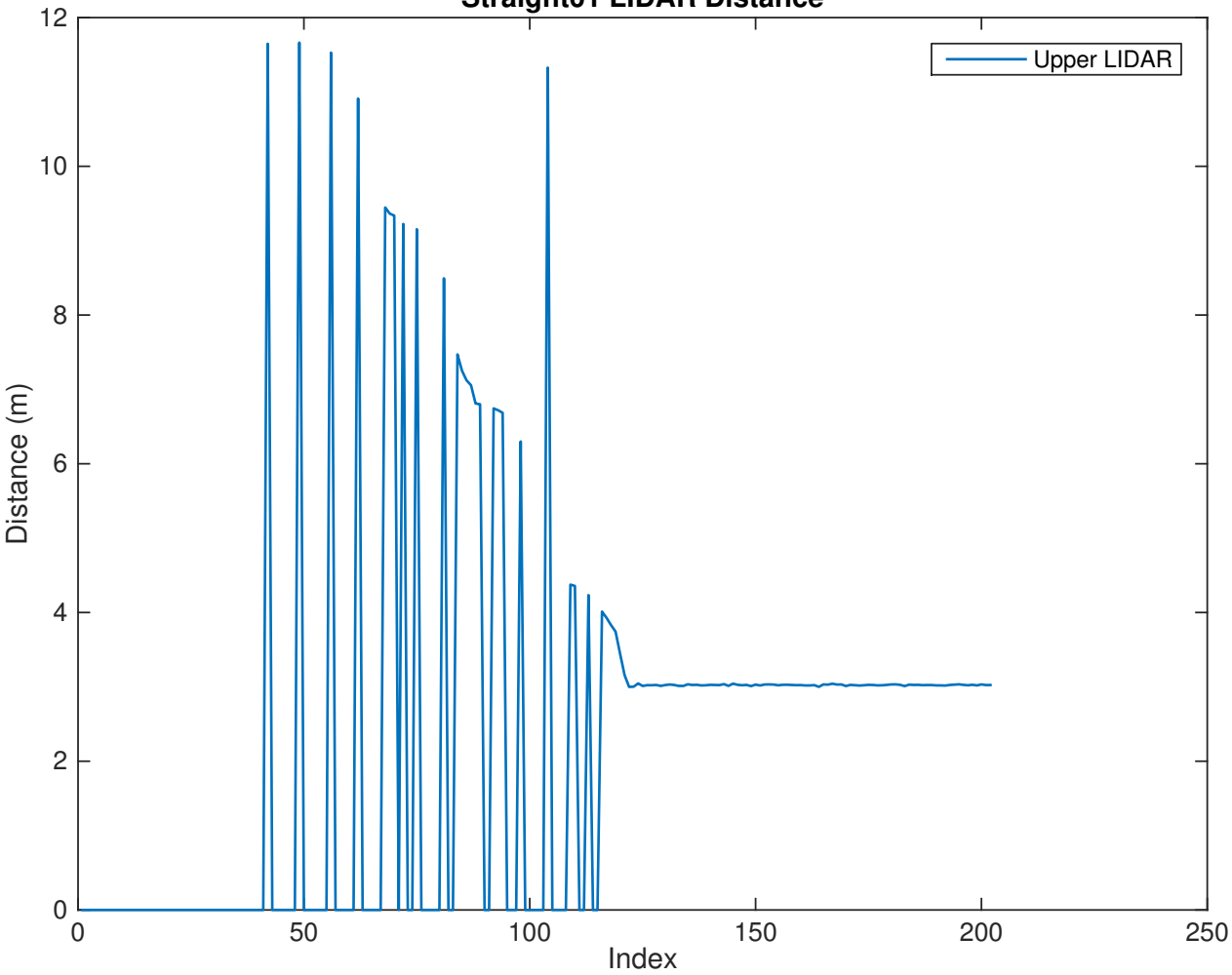
42

false

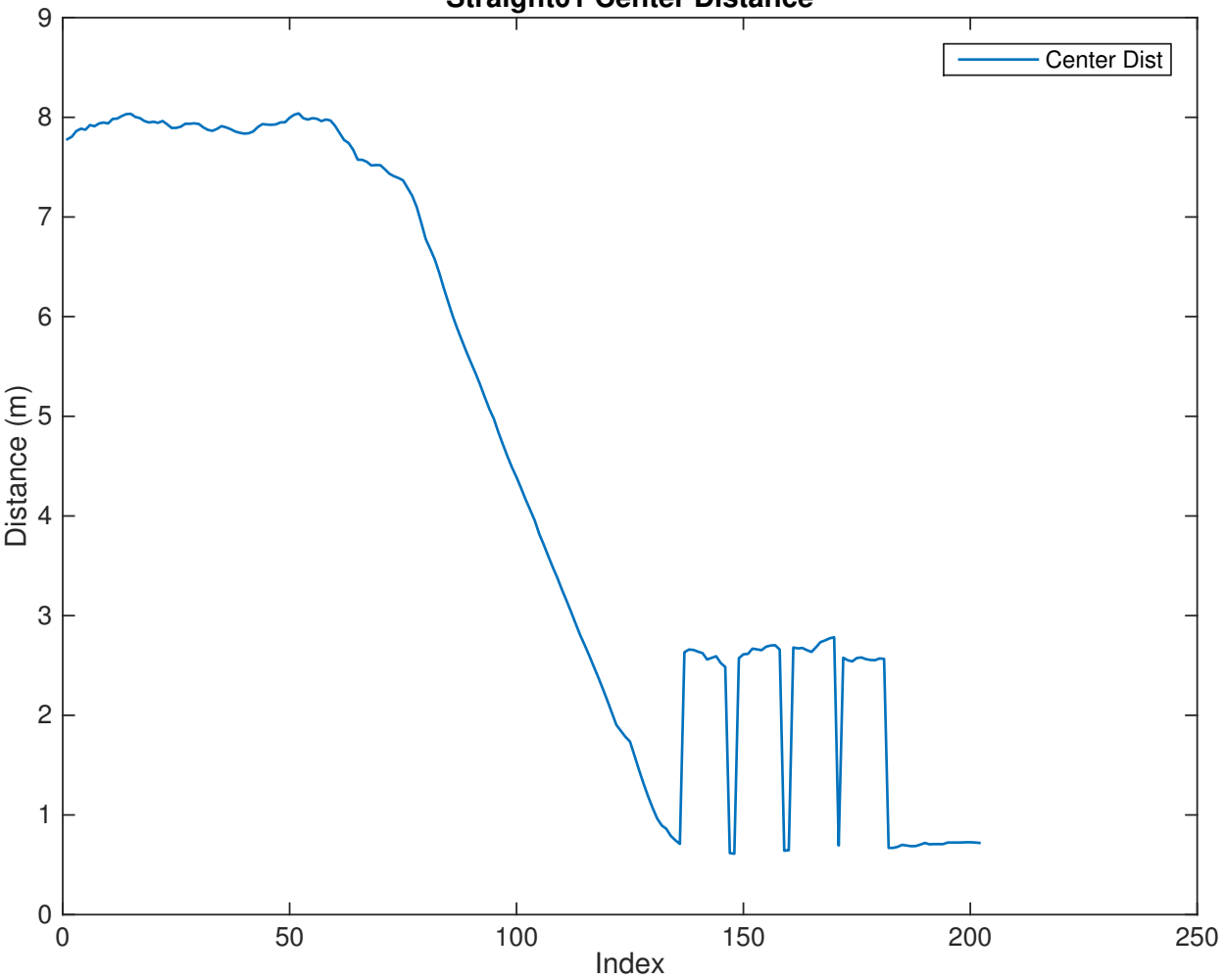
Straight01 Left_Edge vs Right_Edge



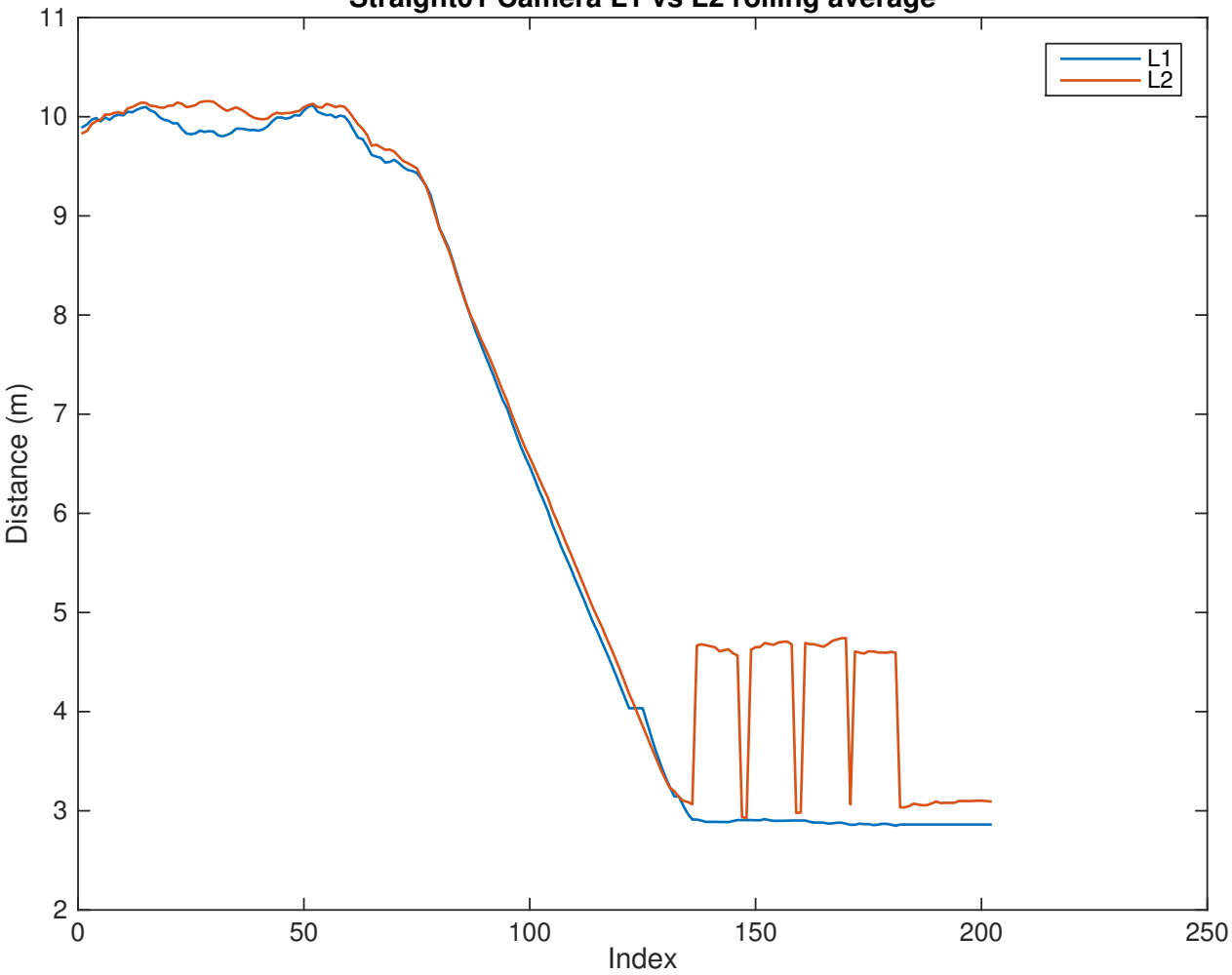
Straight01 LIDAR Distance



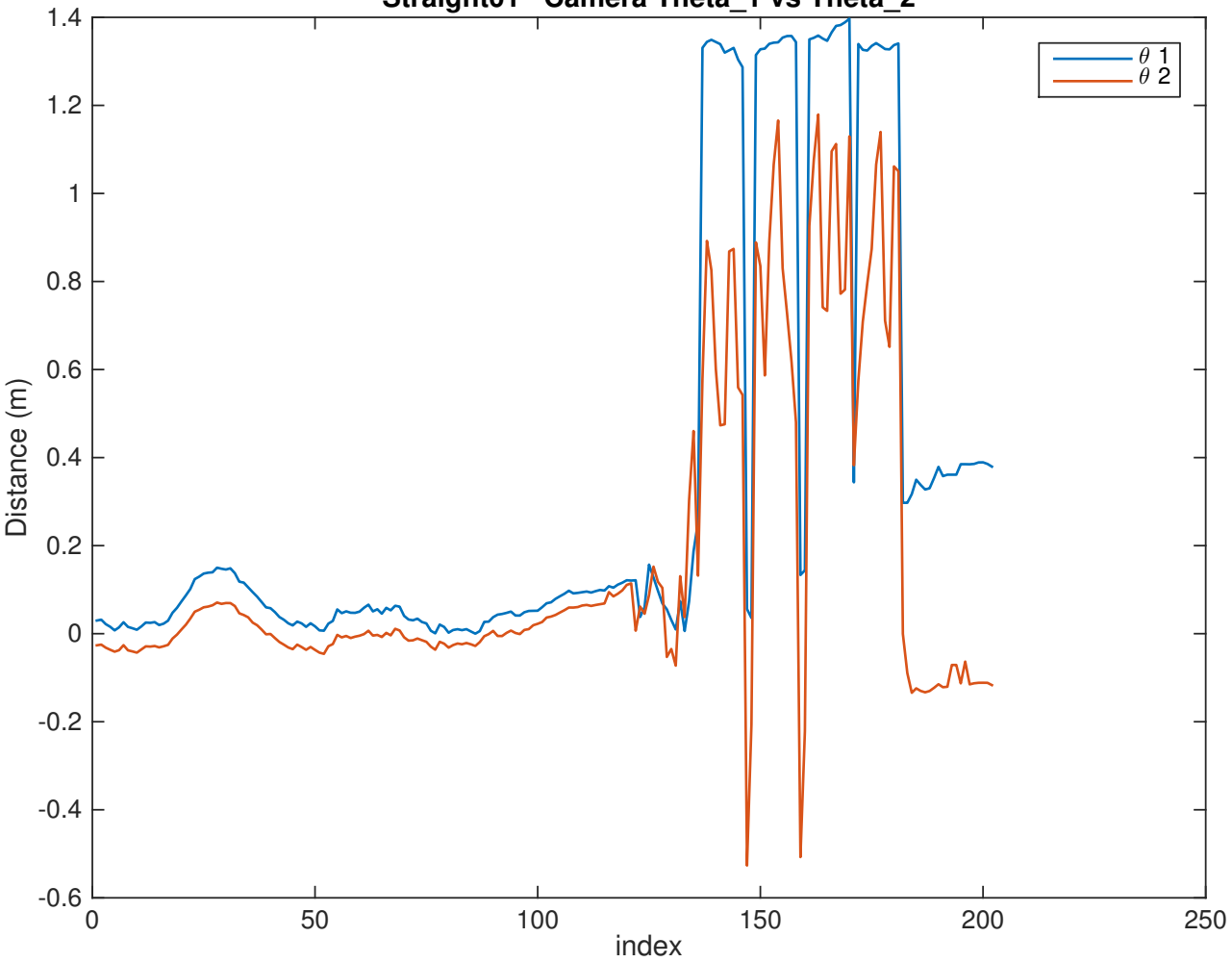
Straight01 Center Distance



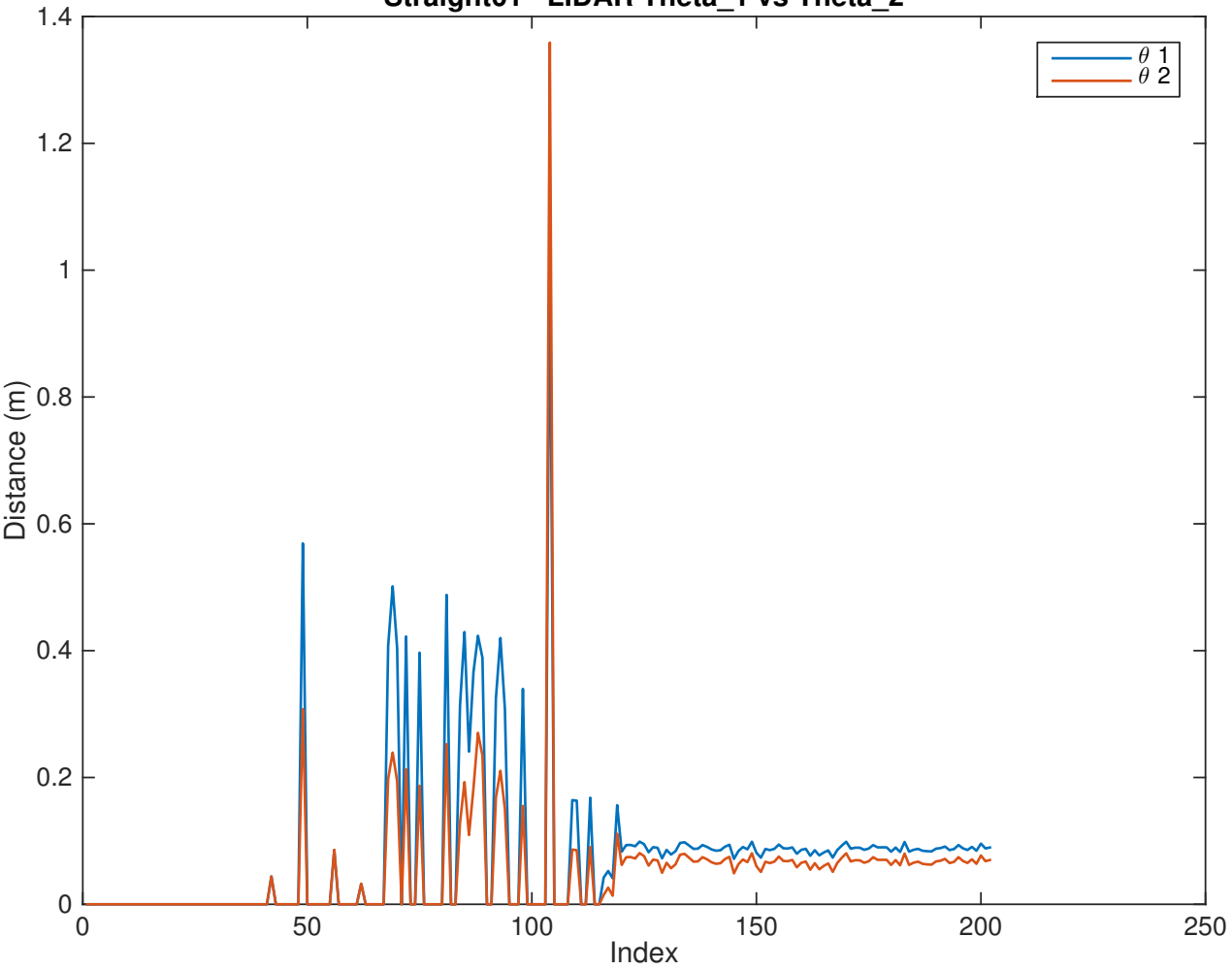
Straight01 Camera L1 vs L2 rolling average



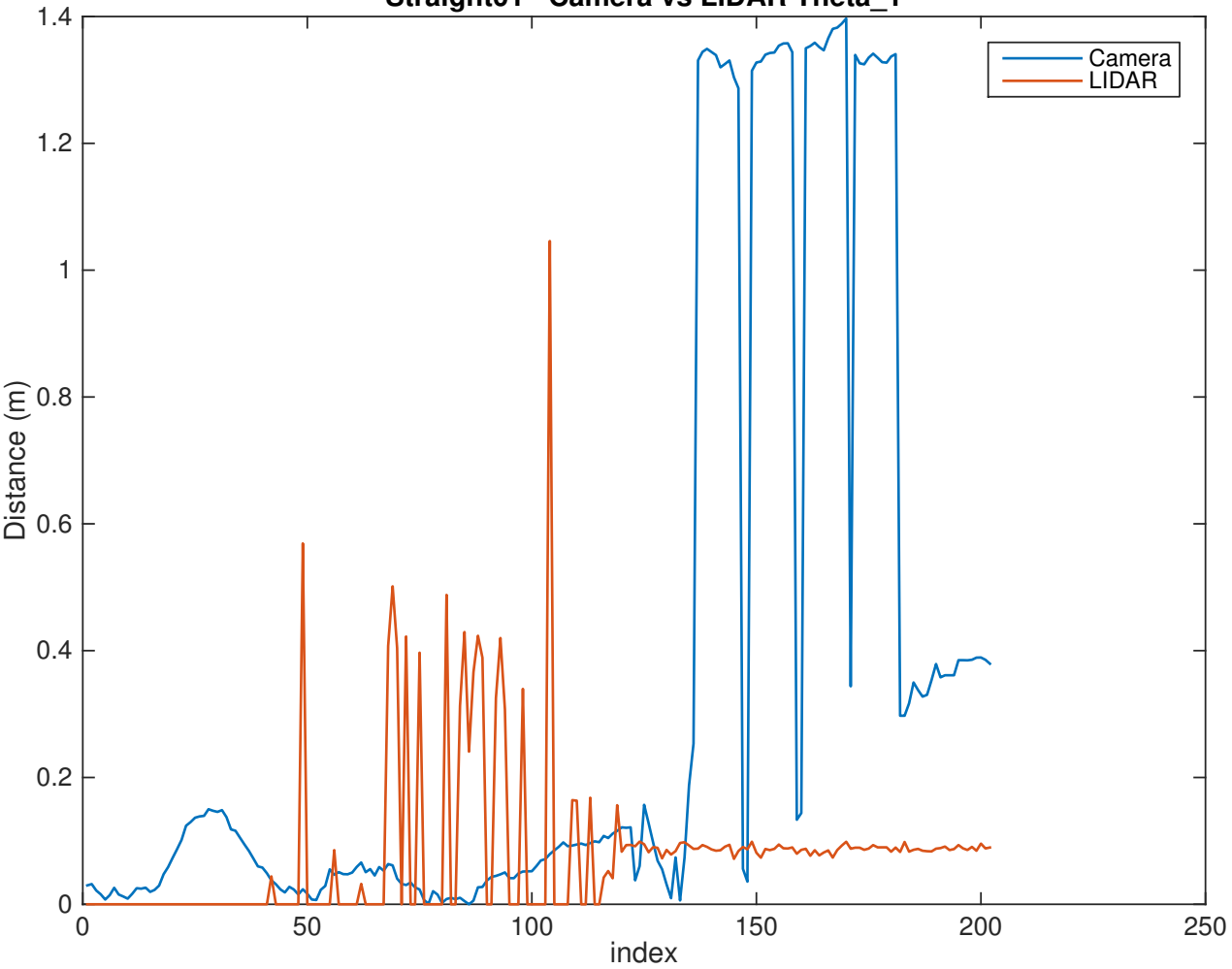
Straight01 Camera Theta_1 vs Theta_2



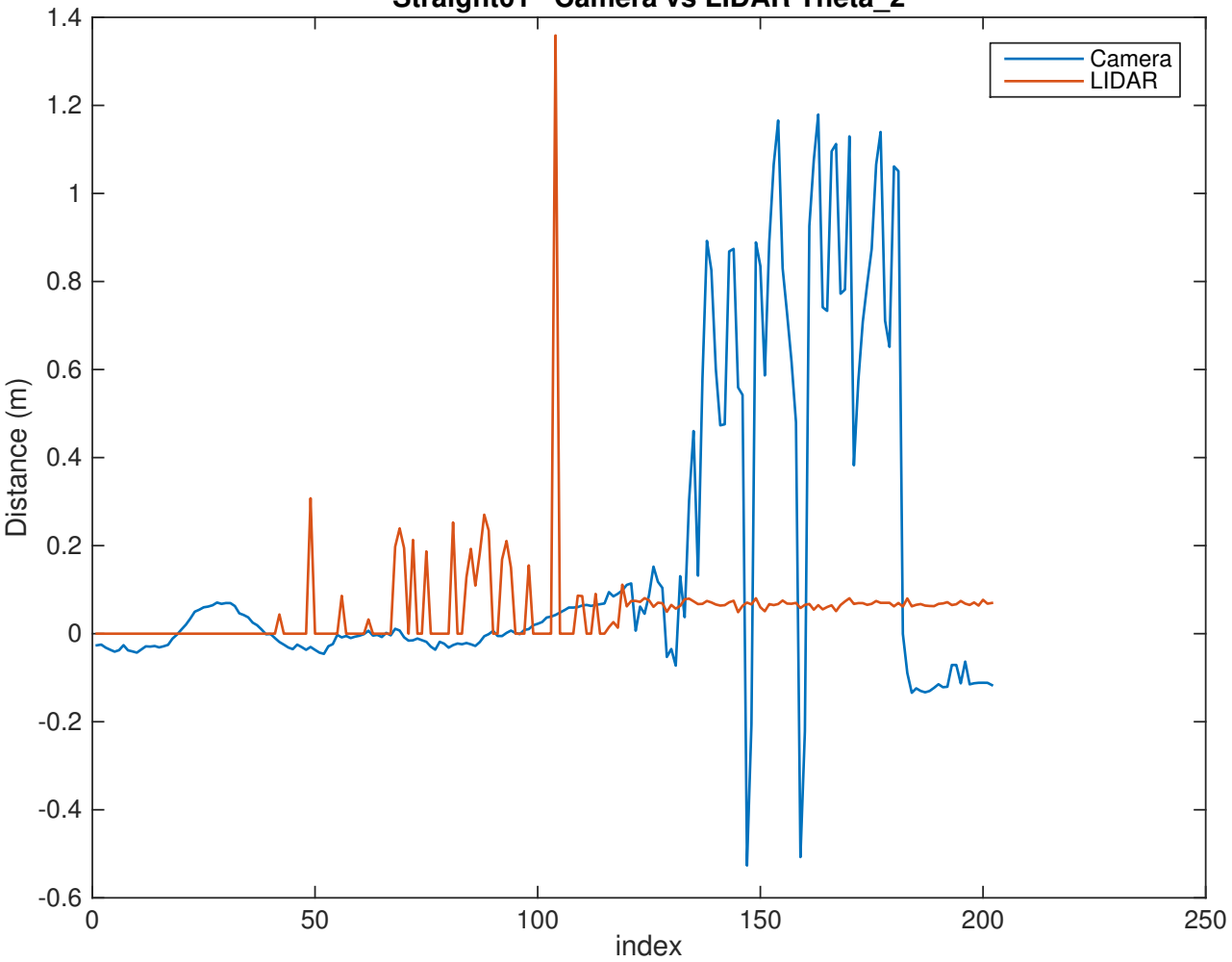
Straight01 LIDAR Theta_1 vs Theta_2



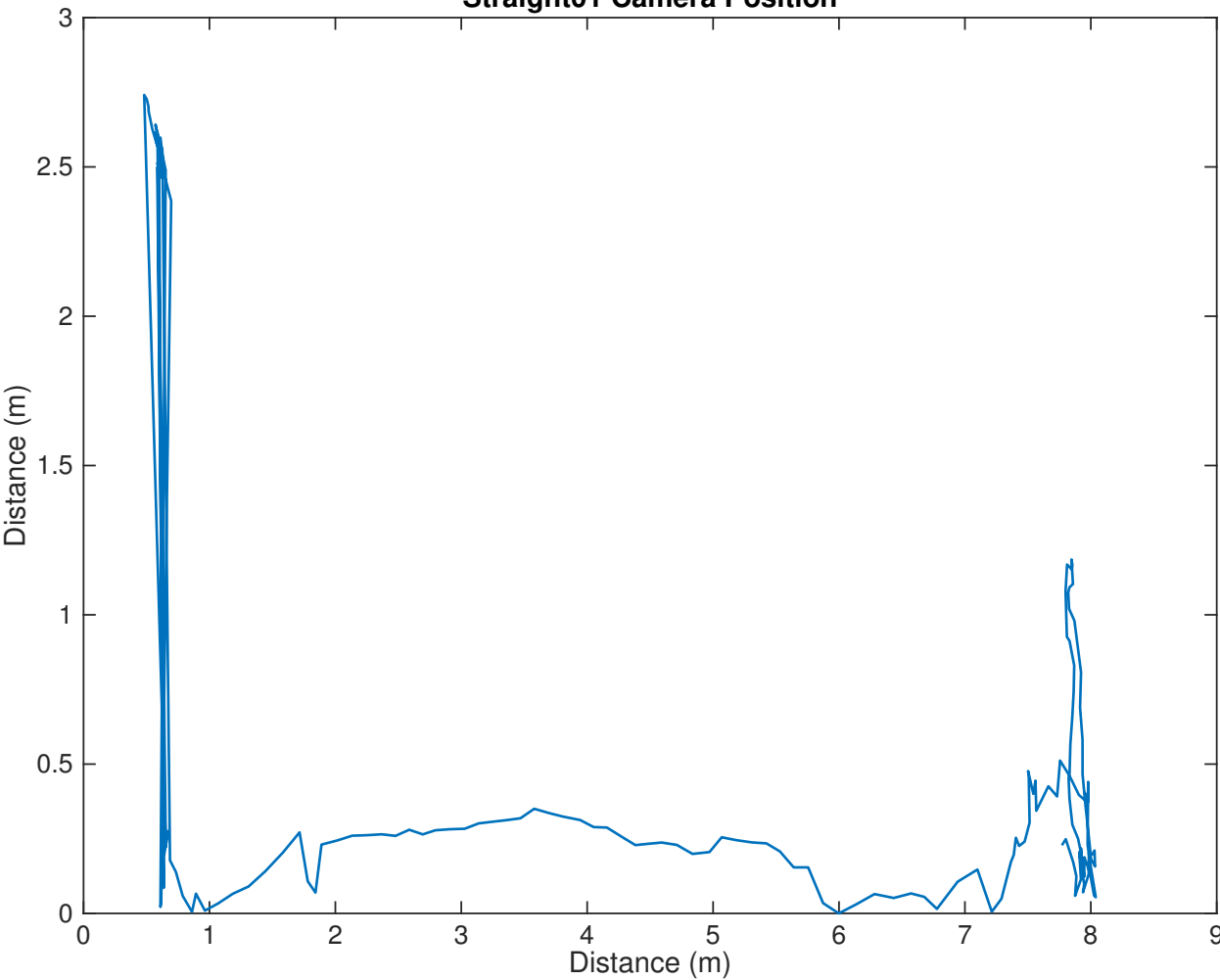
Straight01 Camera vs LIDAR Theta_1



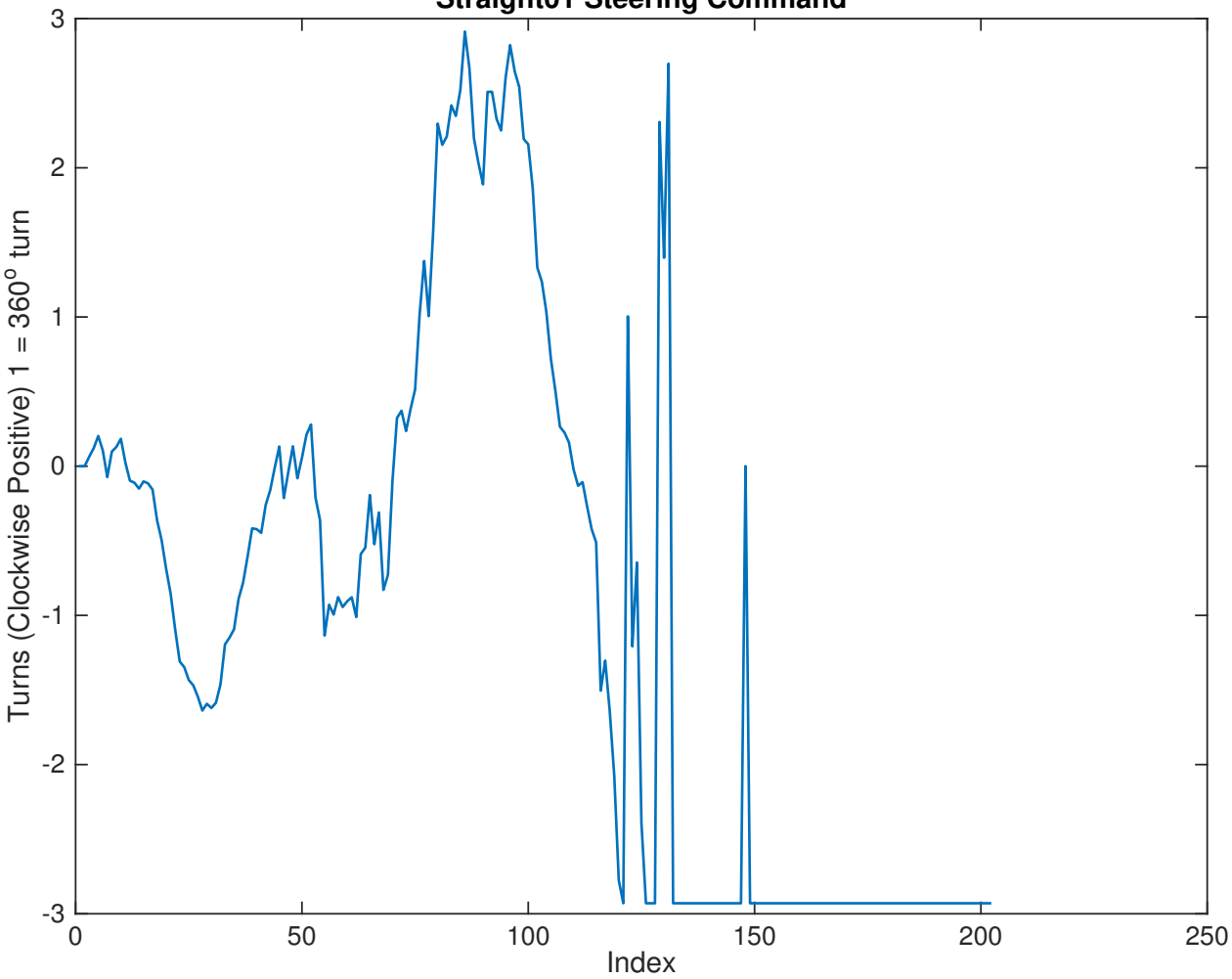
Straight01 Camera vs LIDAR Theta_2



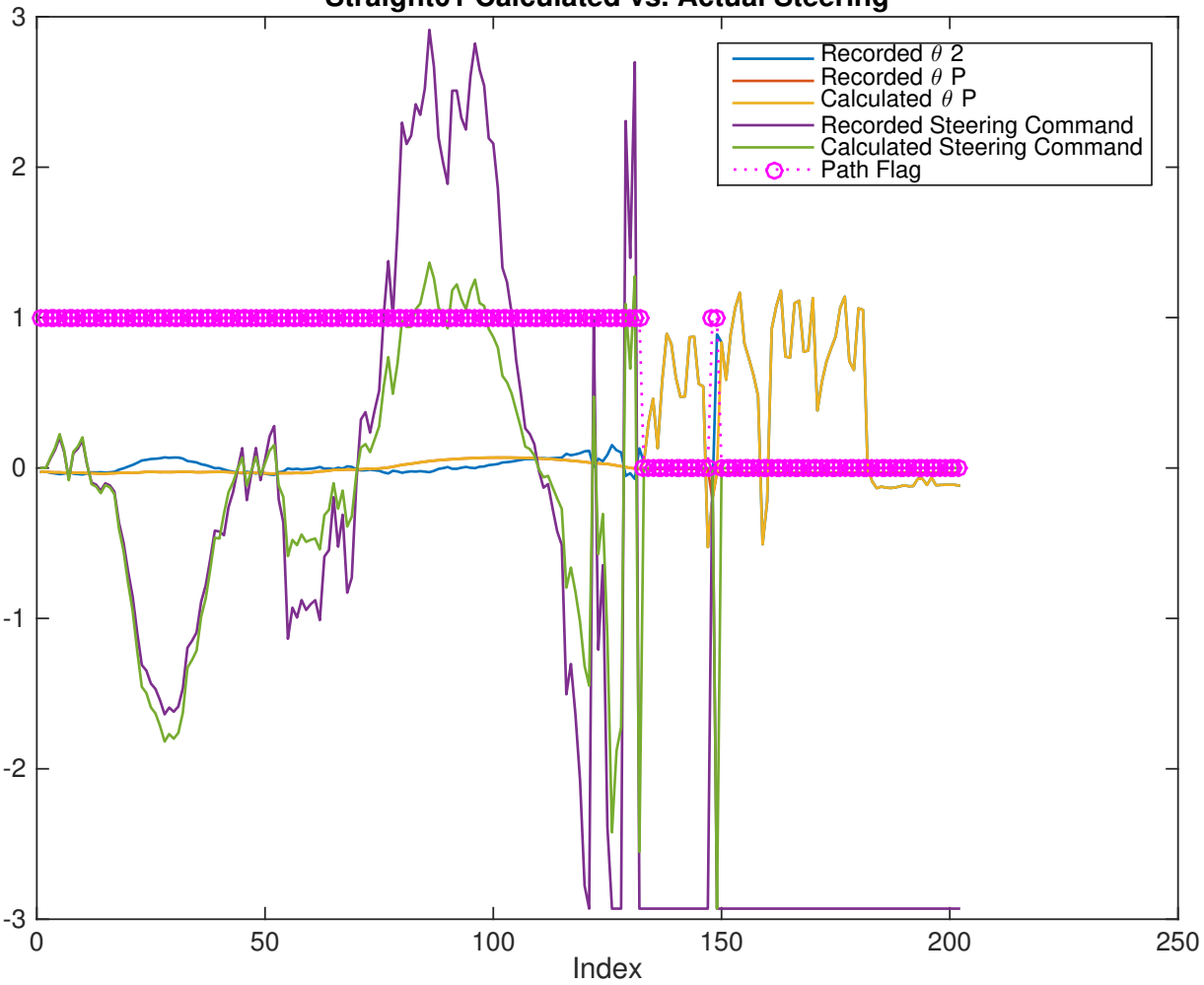
Straight01 Camera Position



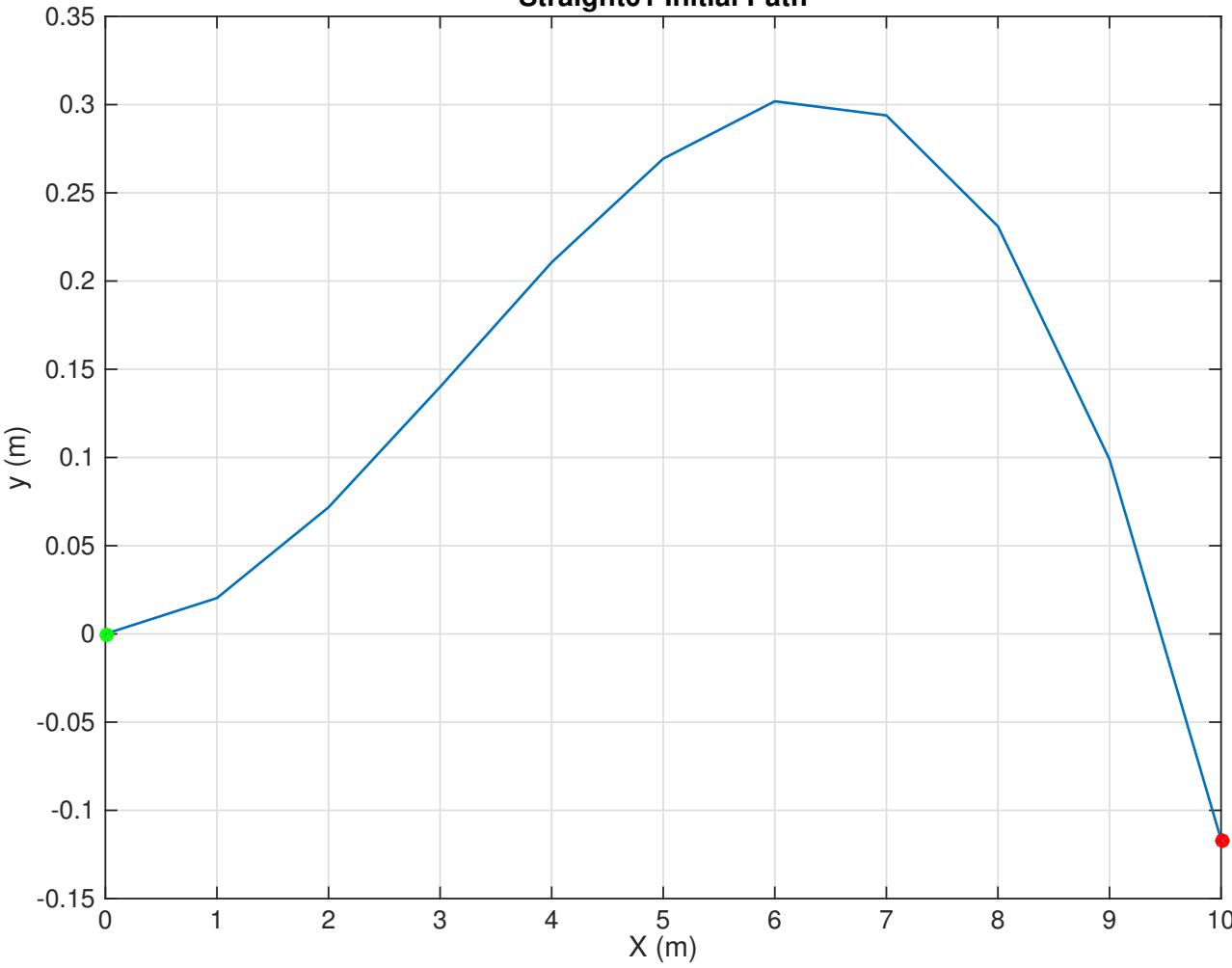
Straight01 Steering Command



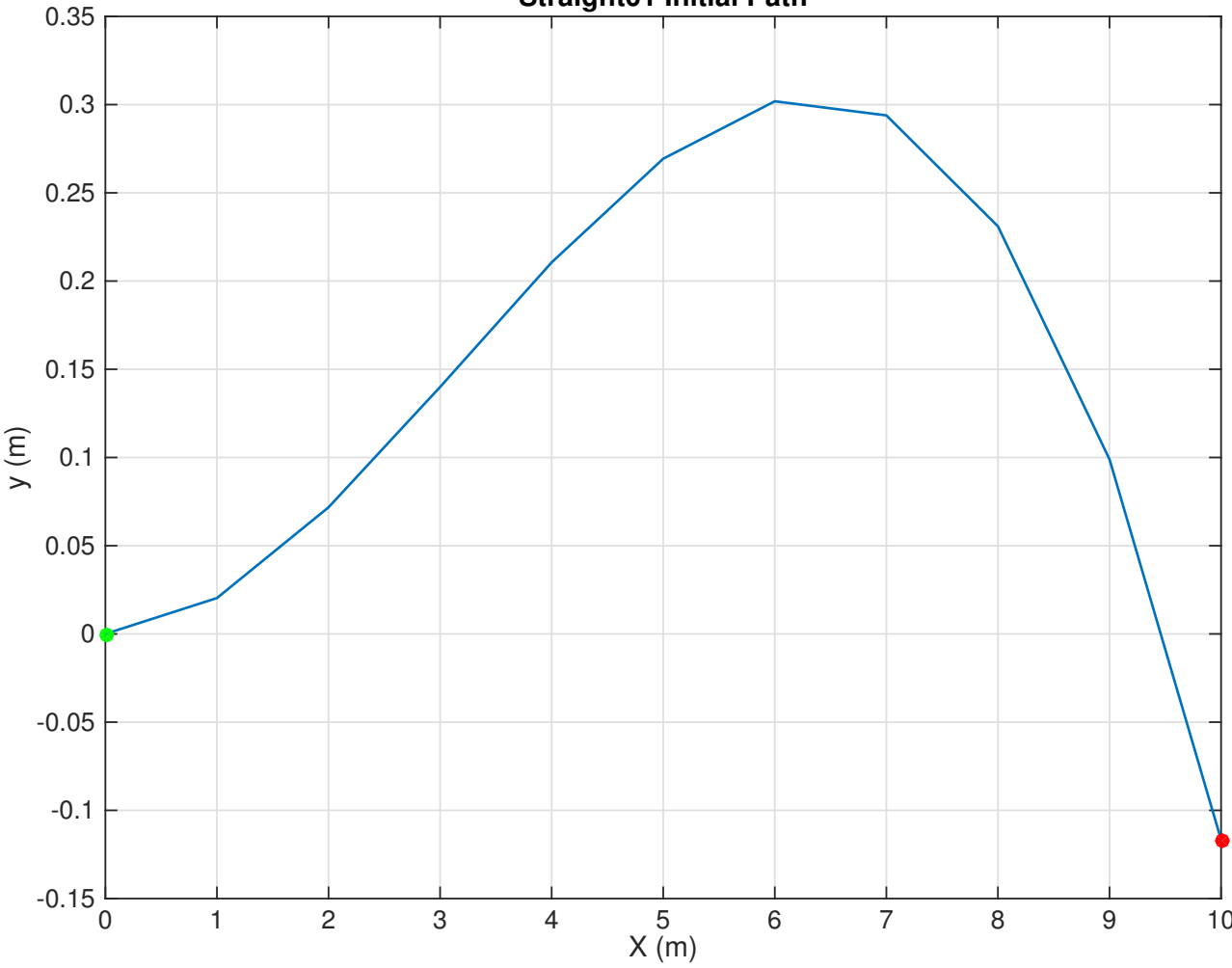
Straight01 Calculated vs. Actual Steering



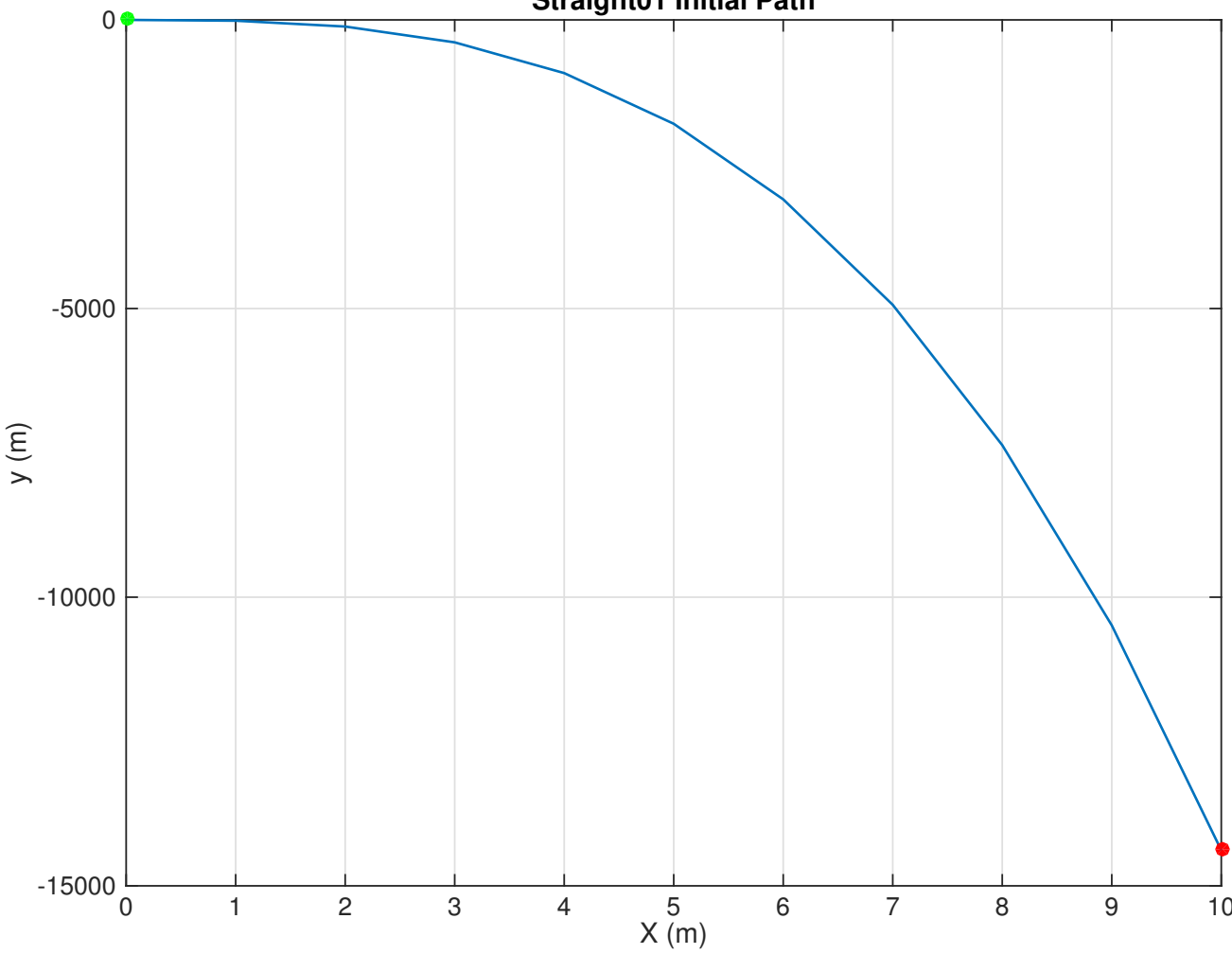
Straight01 Initial Path



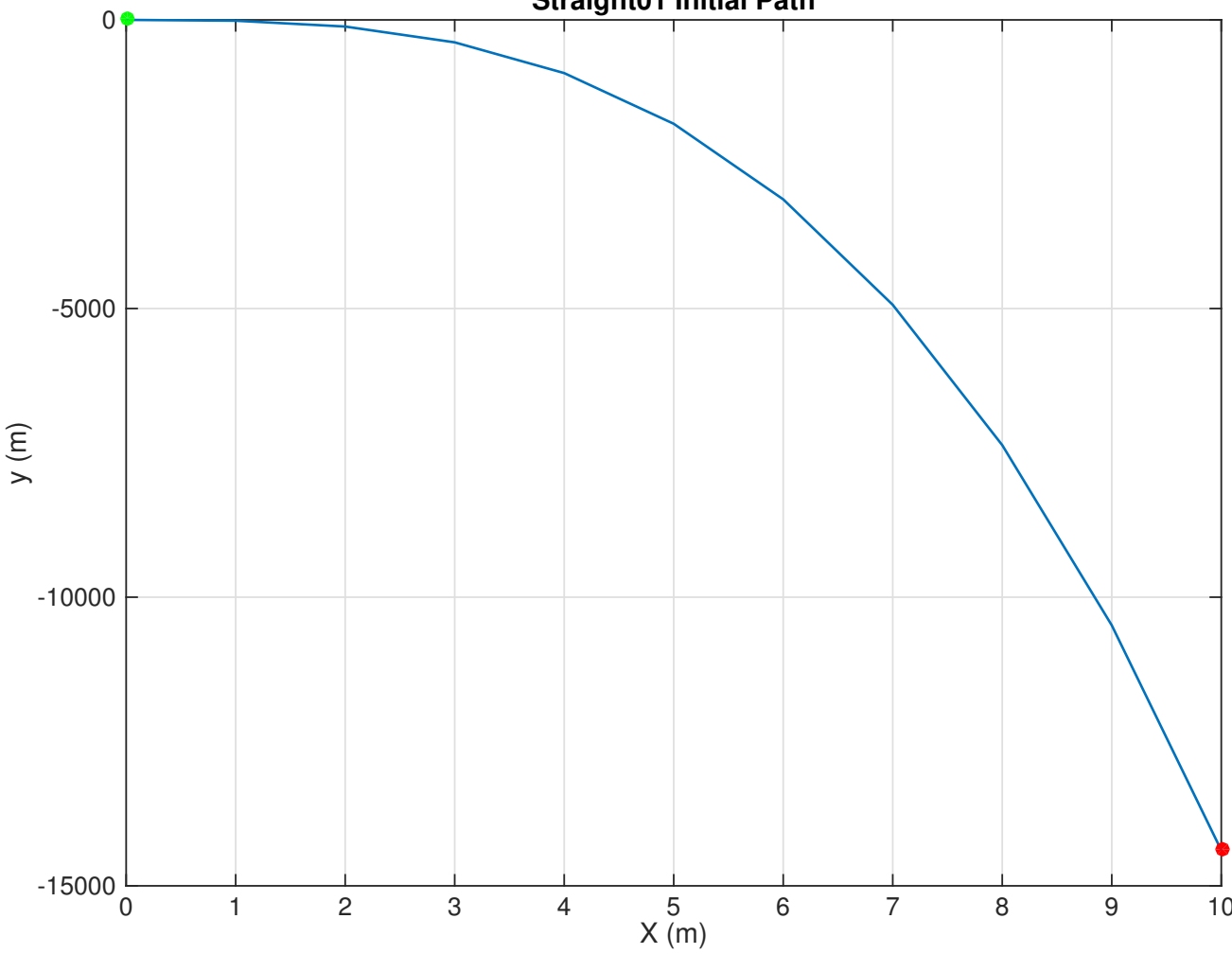
Straight01 Initial Path



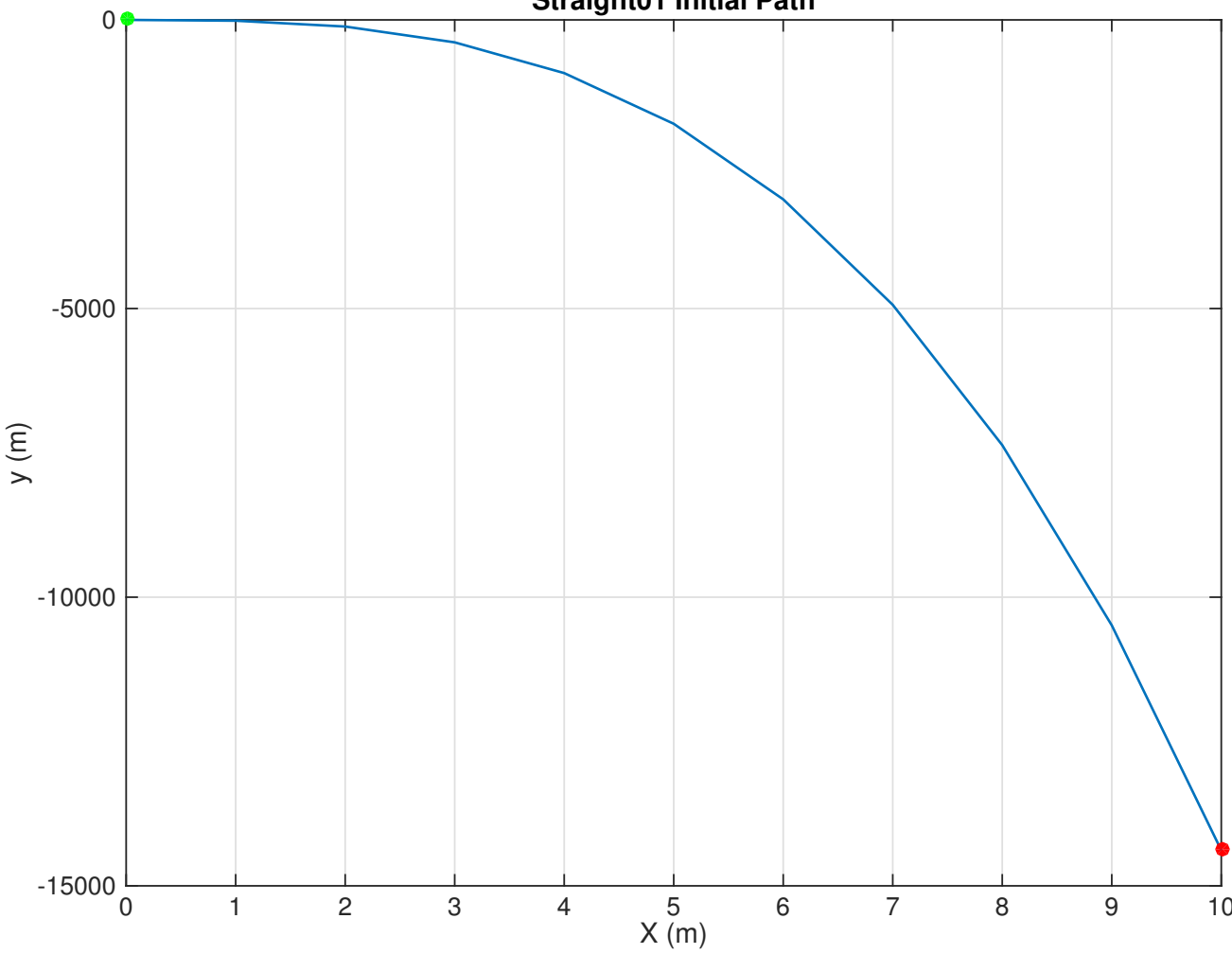
Straight01 Initial Path



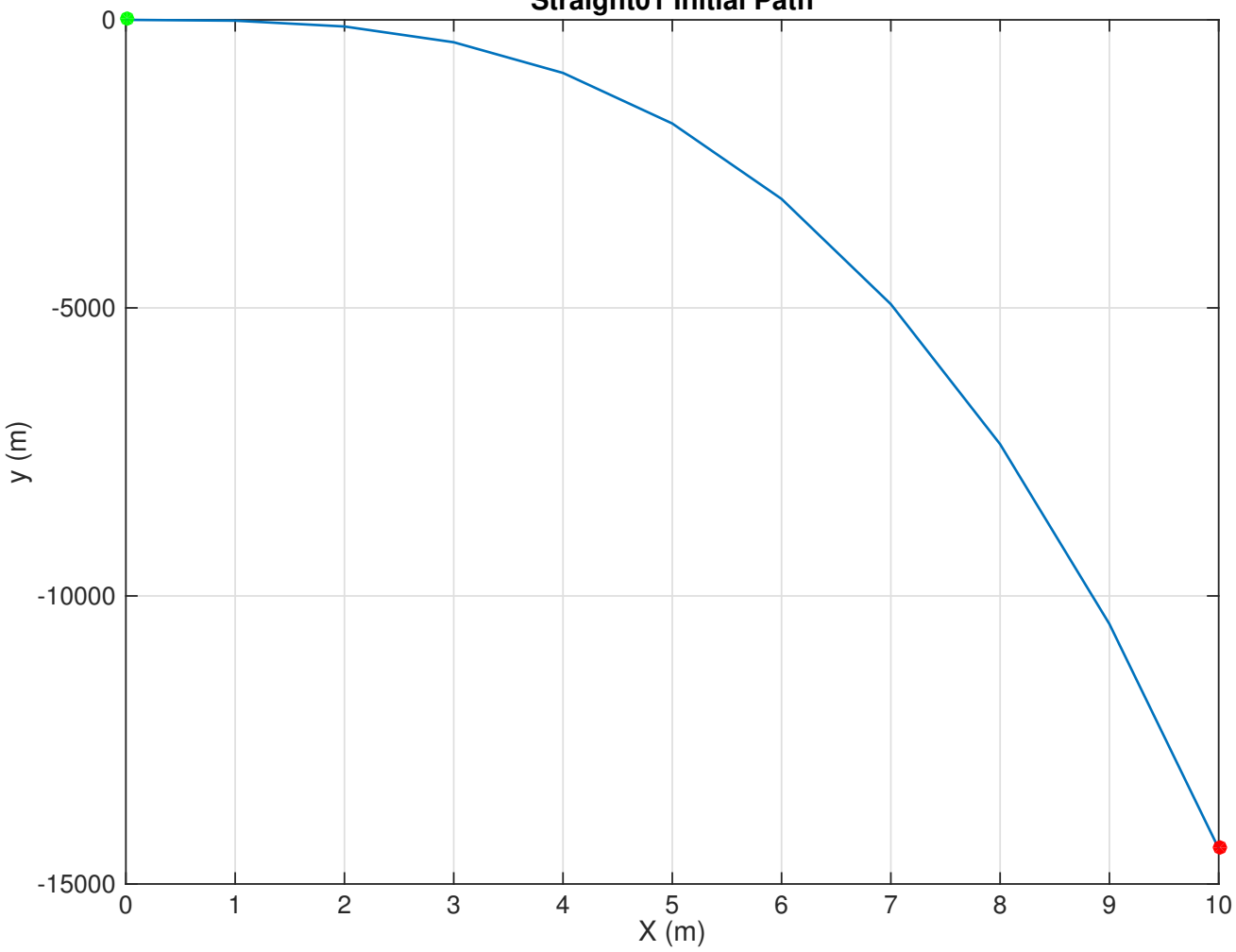
Straight01 Initial Path



Straight01 Initial Path



Straight01 Initial Path



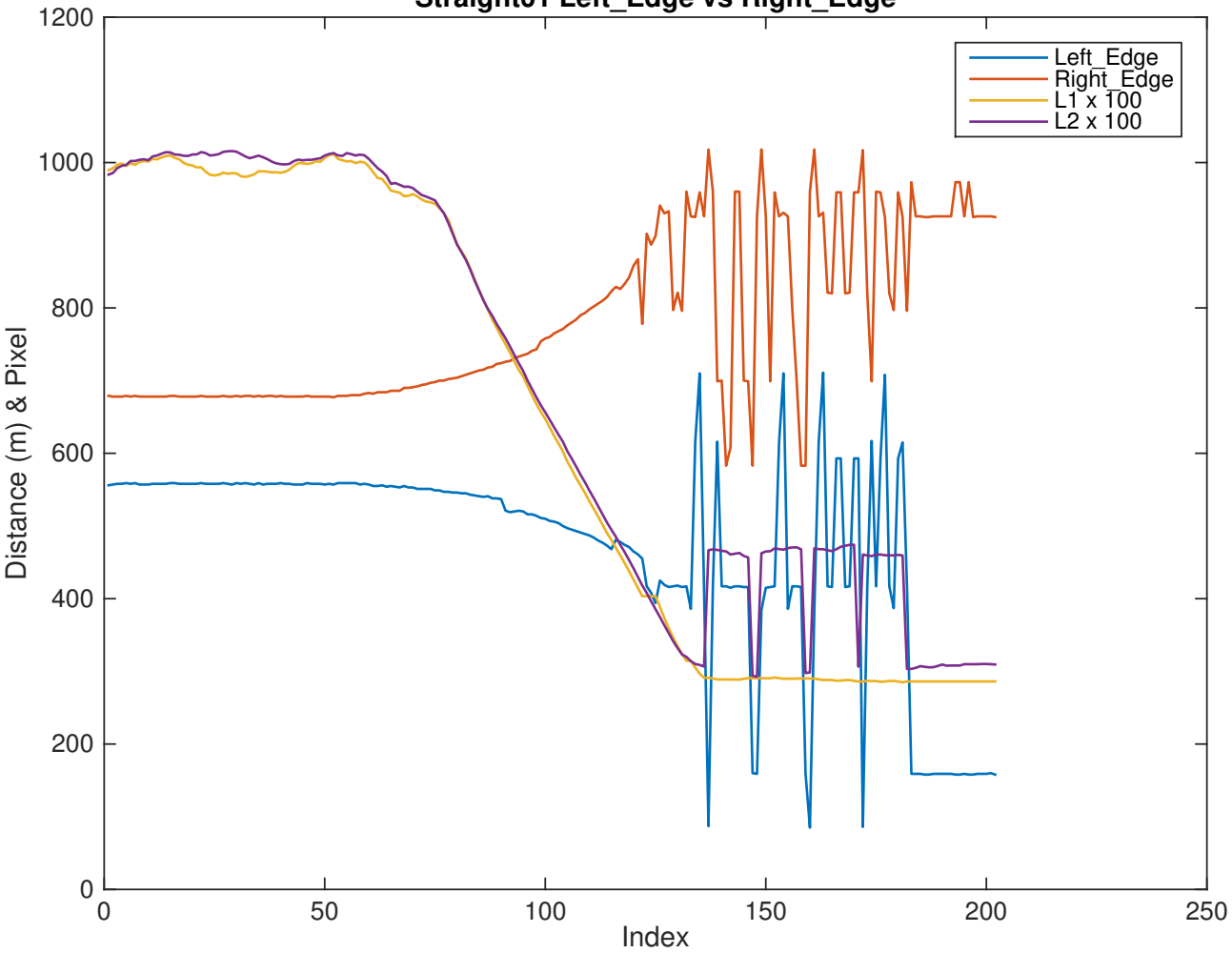
Number_Of_Unique_Paths

King_Pin_Detected

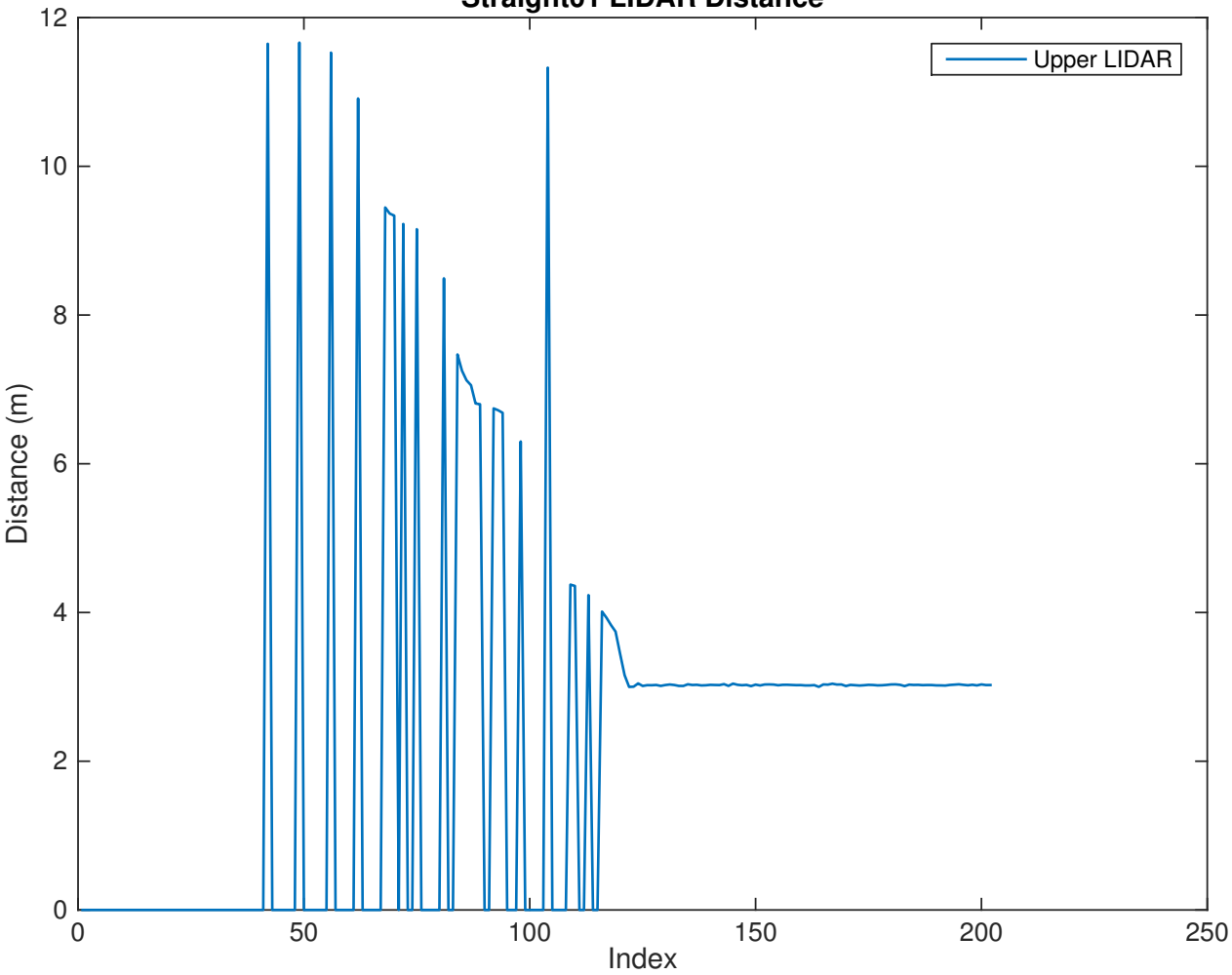
2

false

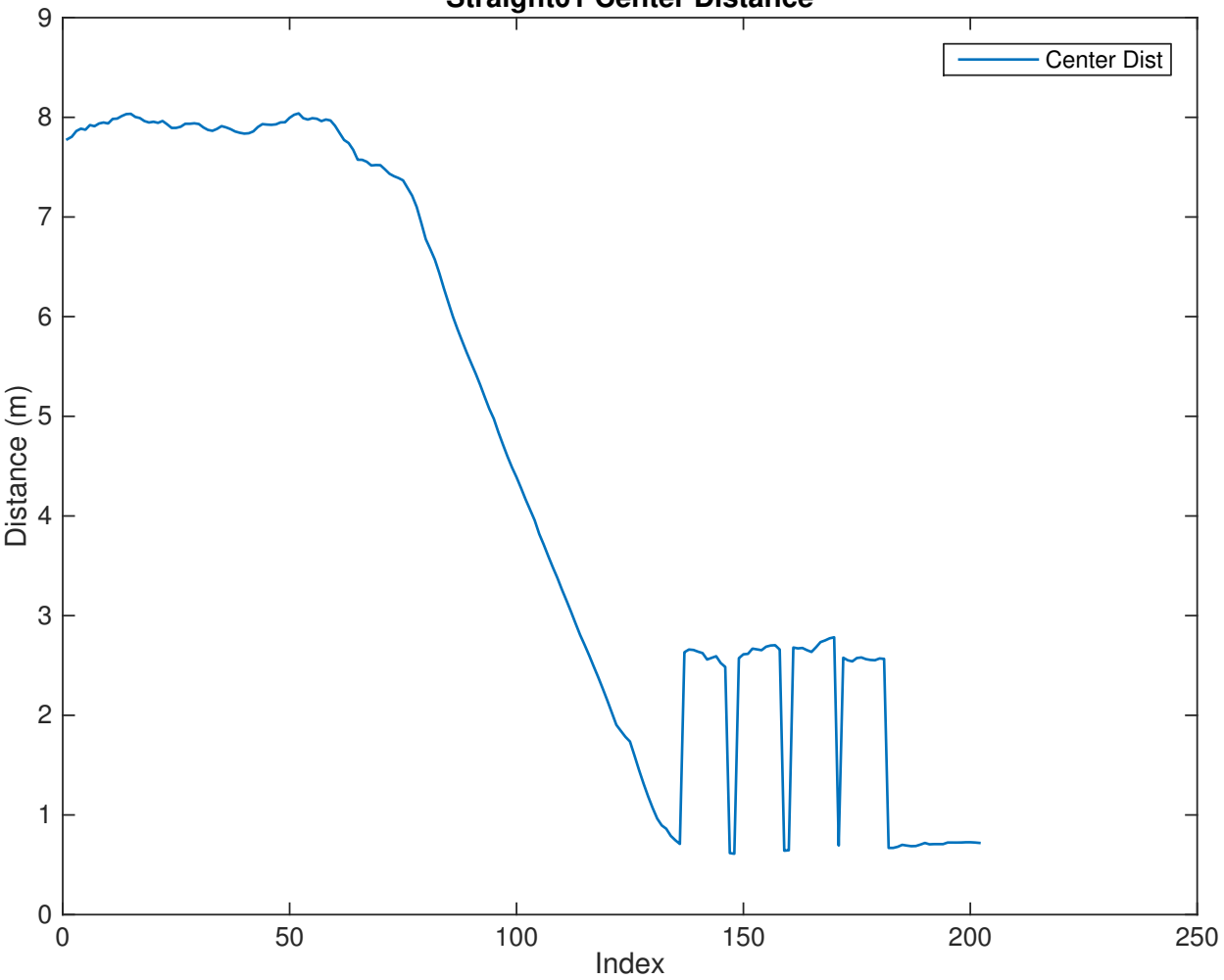
Straight01 Left_Edge vs Right_Edge



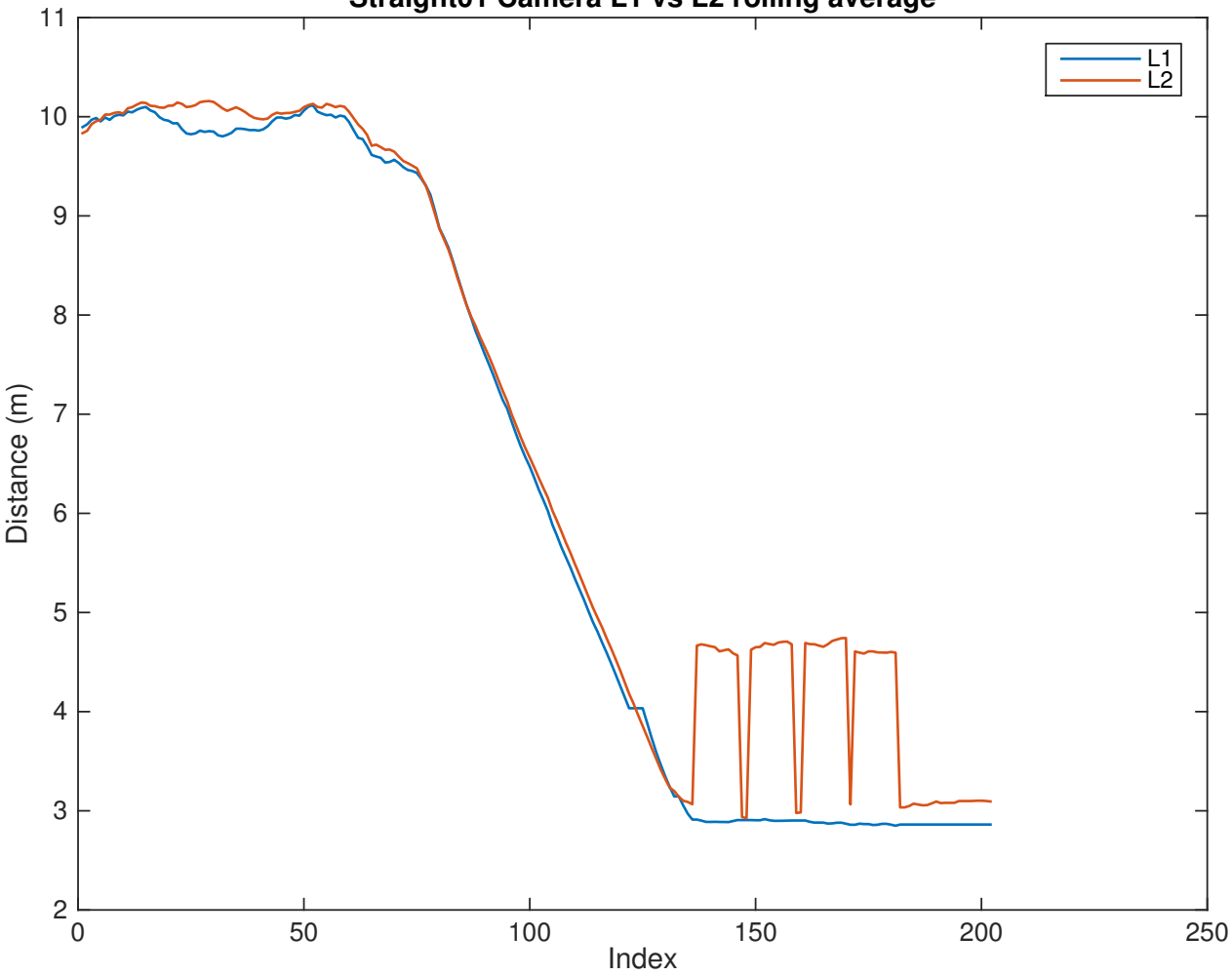
Straight01 LIDAR Distance



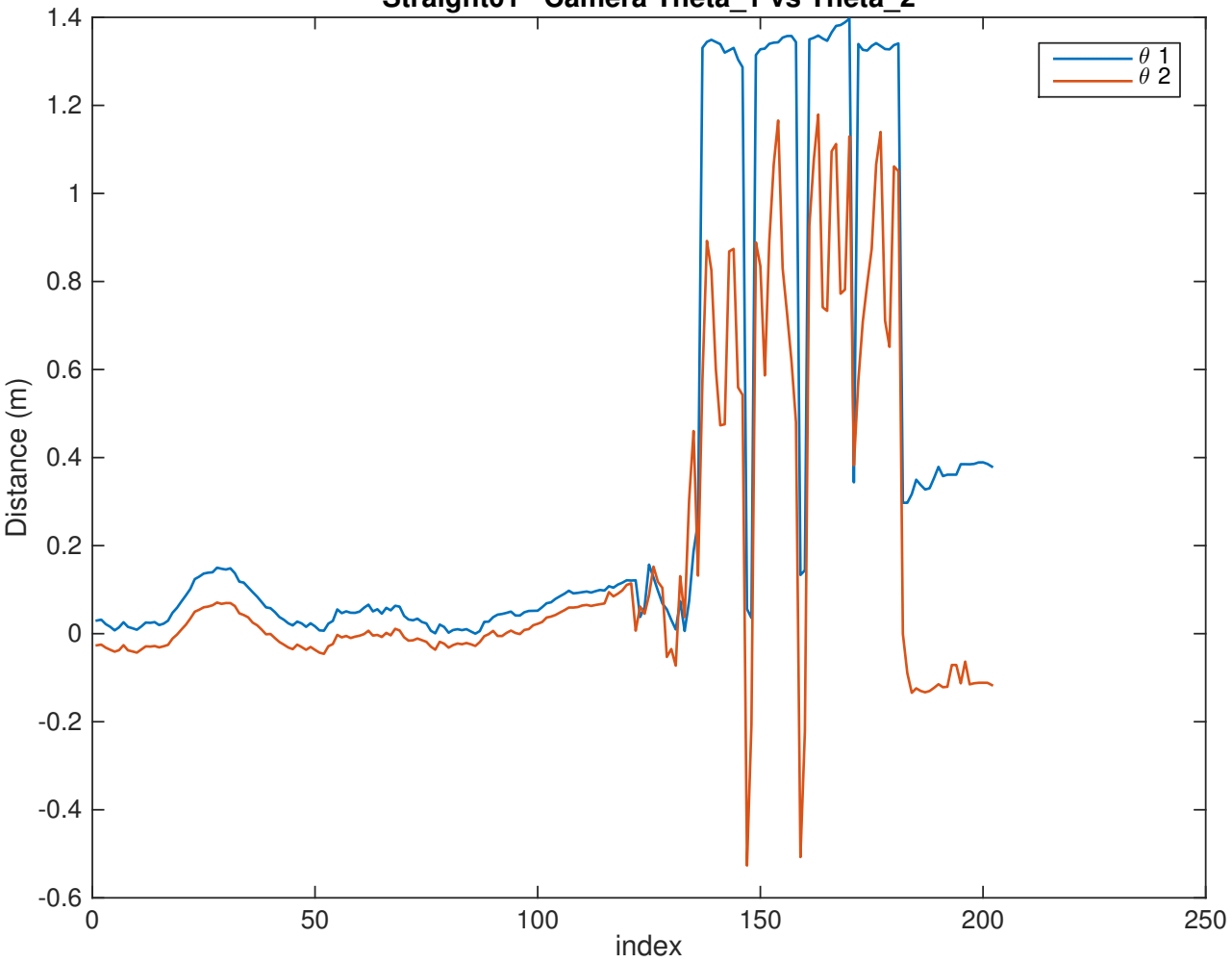
Straight01 Center Distance



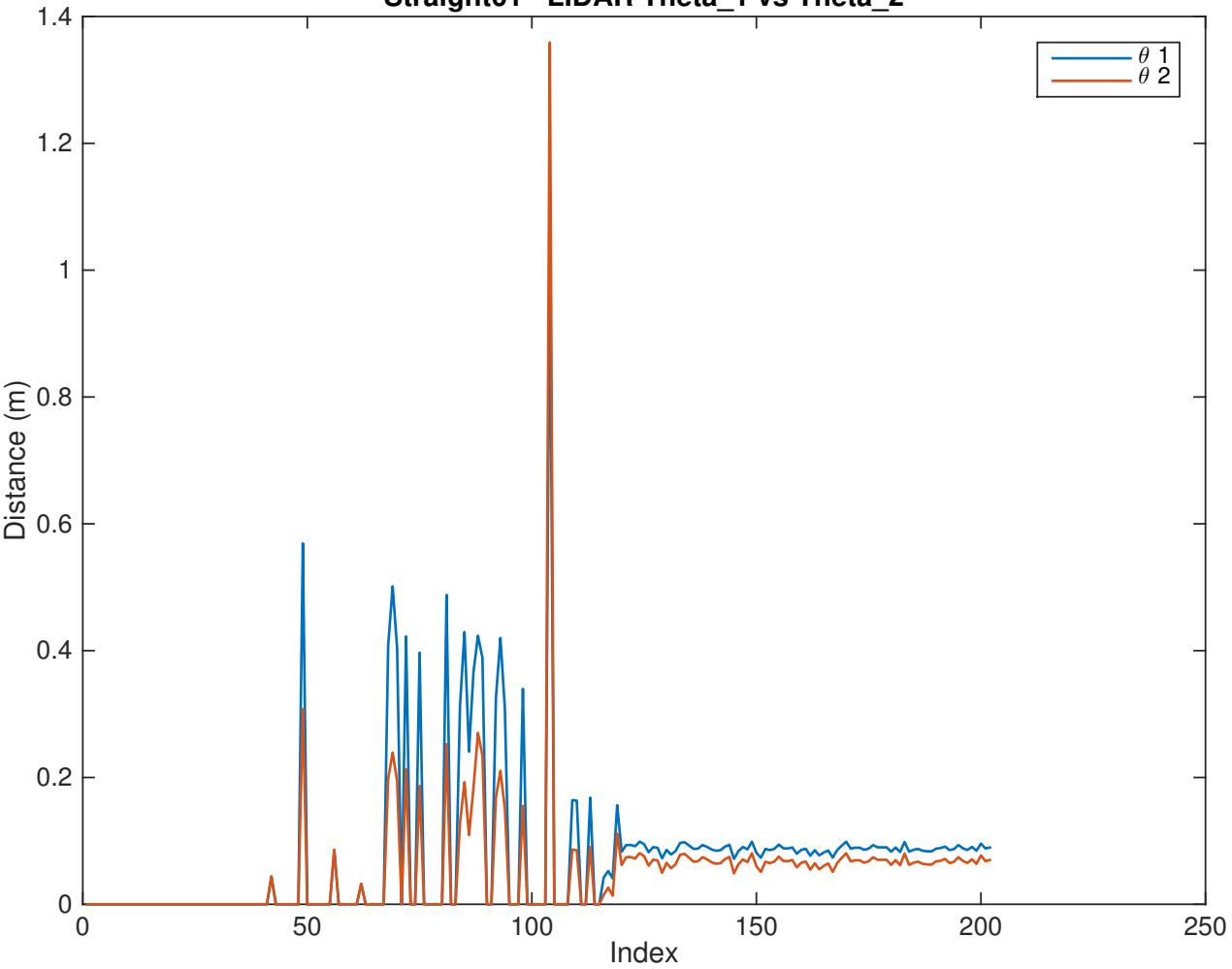
Straight01 Camera L1 vs L2 rolling average



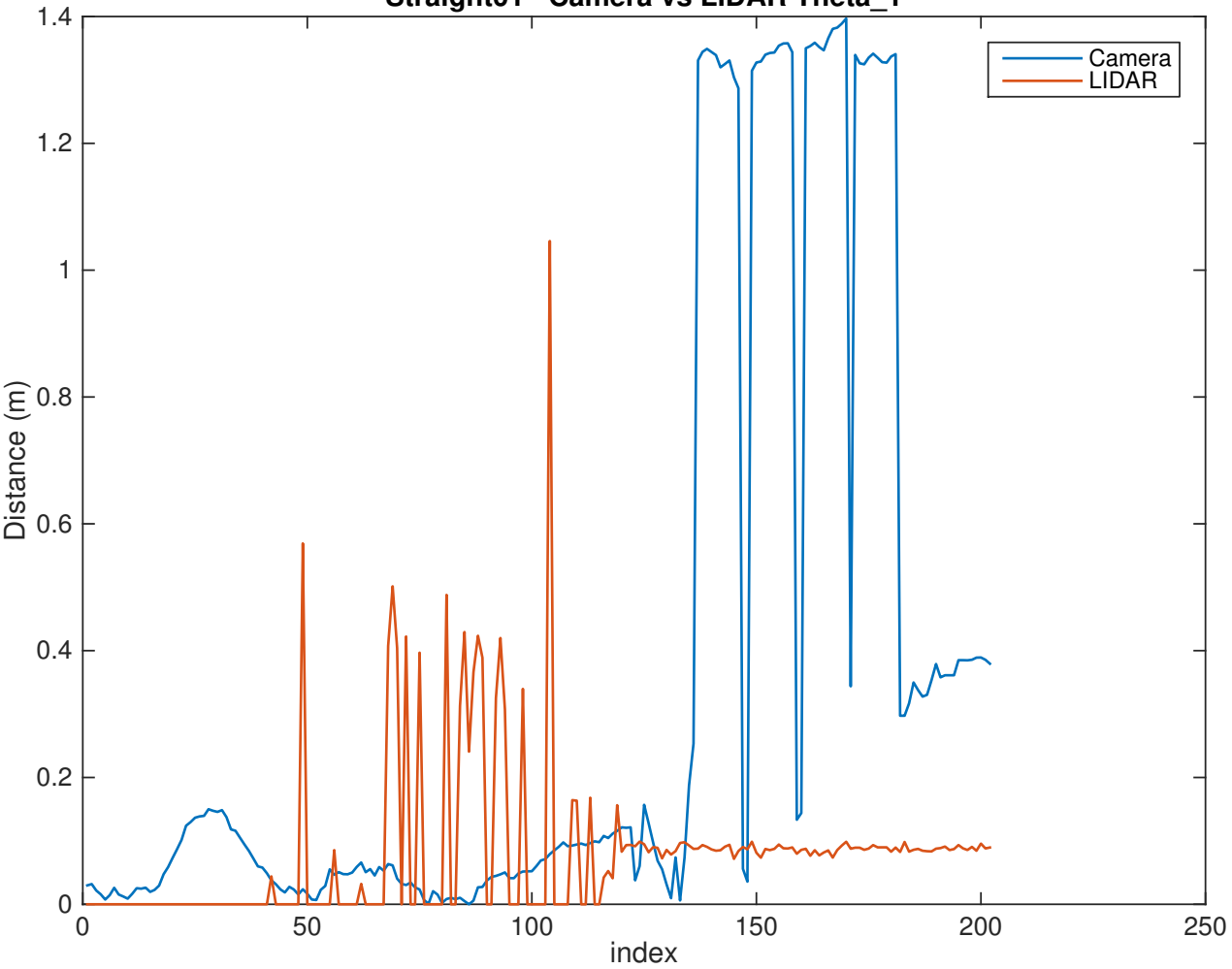
Straight01 Camera Theta_1 vs Theta_2



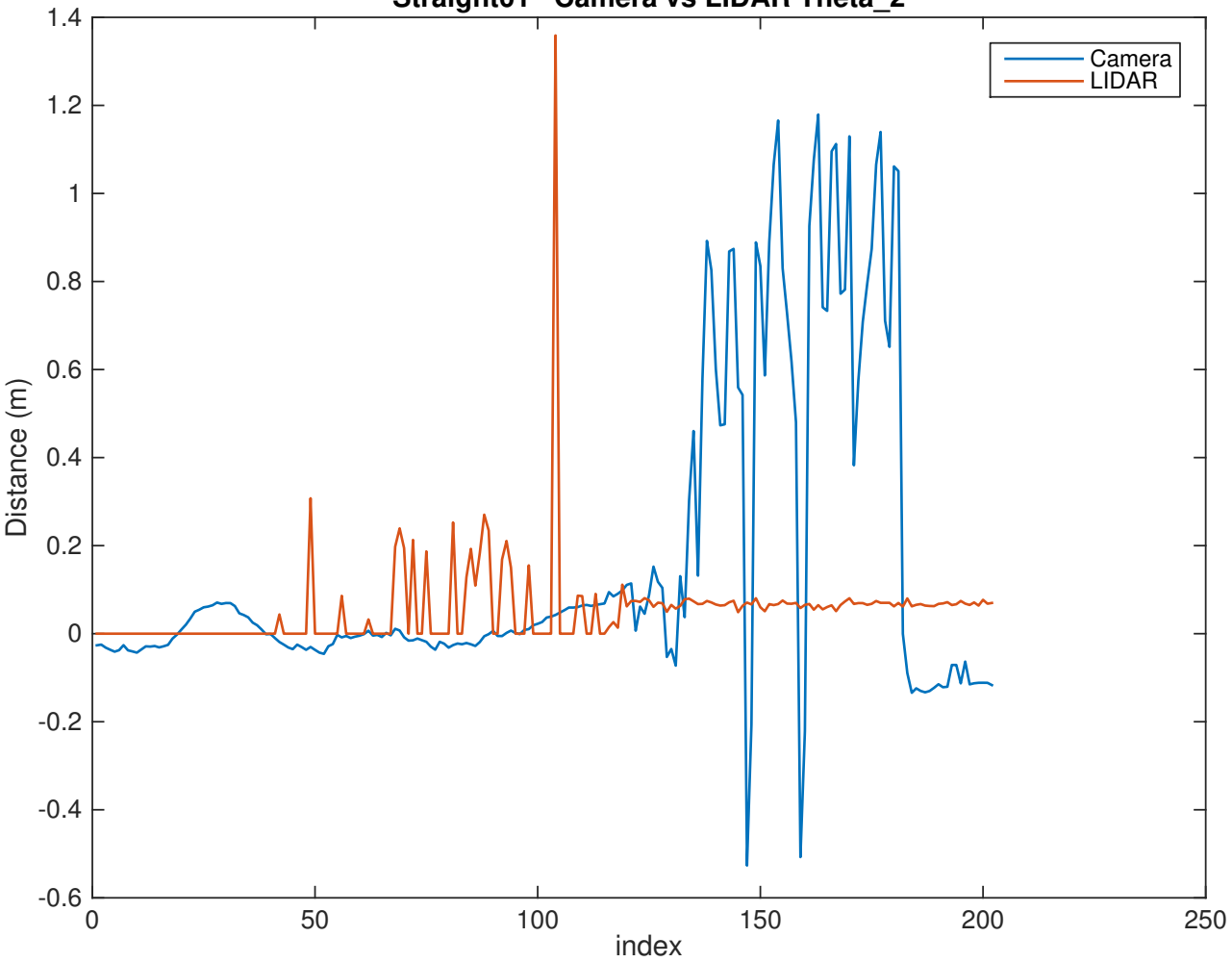
Straight01 LIDAR Theta_1 vs Theta_2



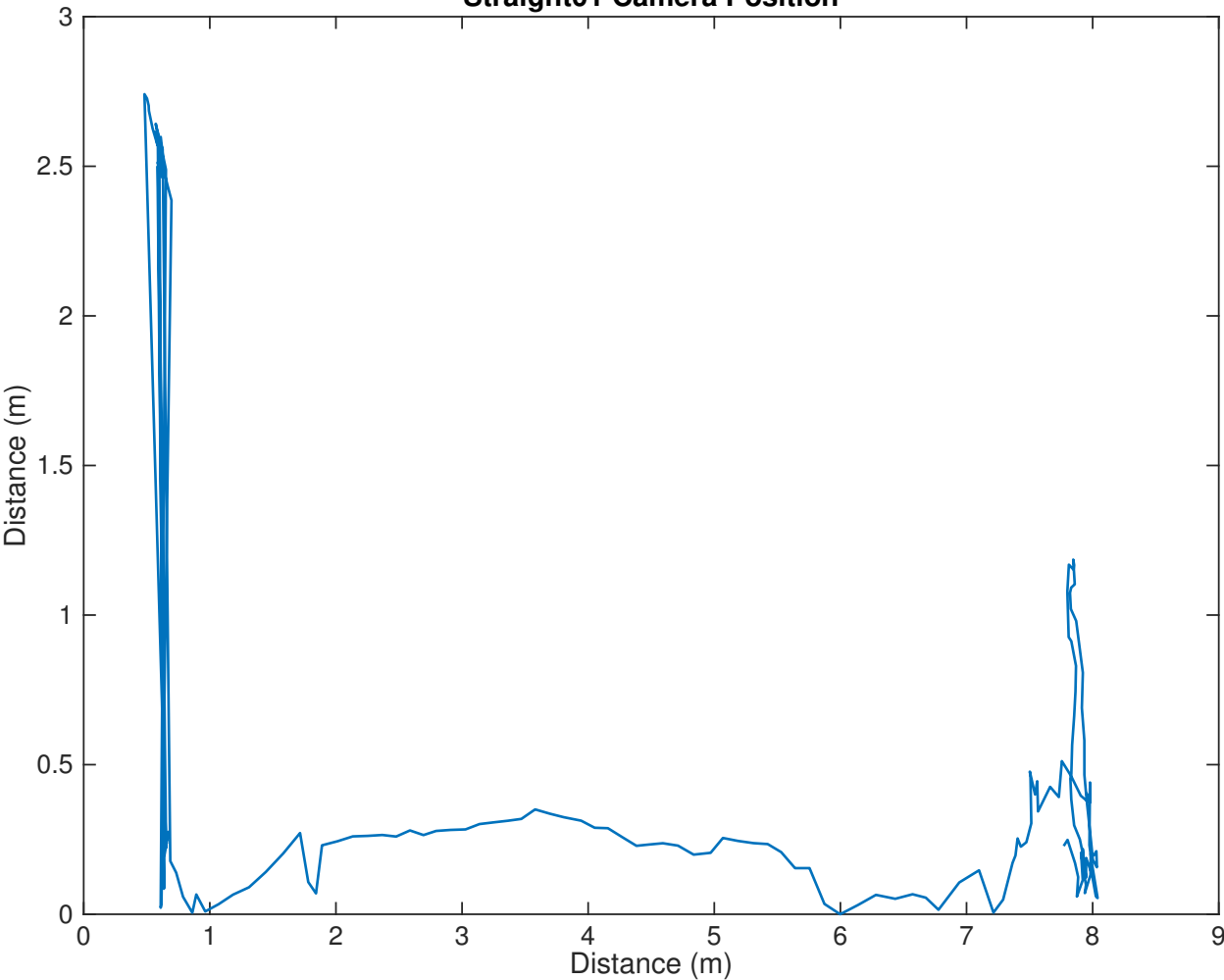
Straight01 Camera vs LIDAR Theta_1



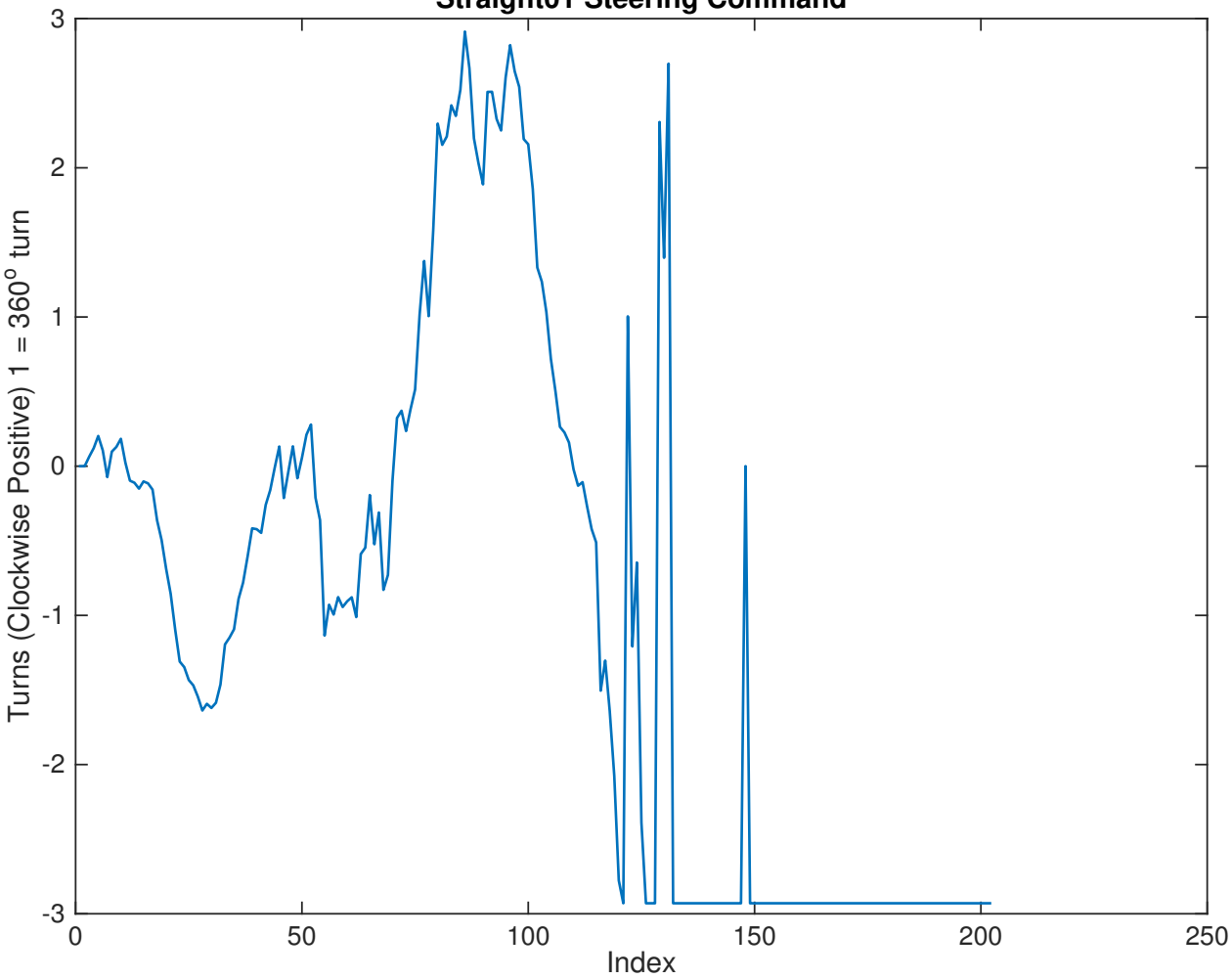
Straight01 Camera vs LIDAR Theta_2



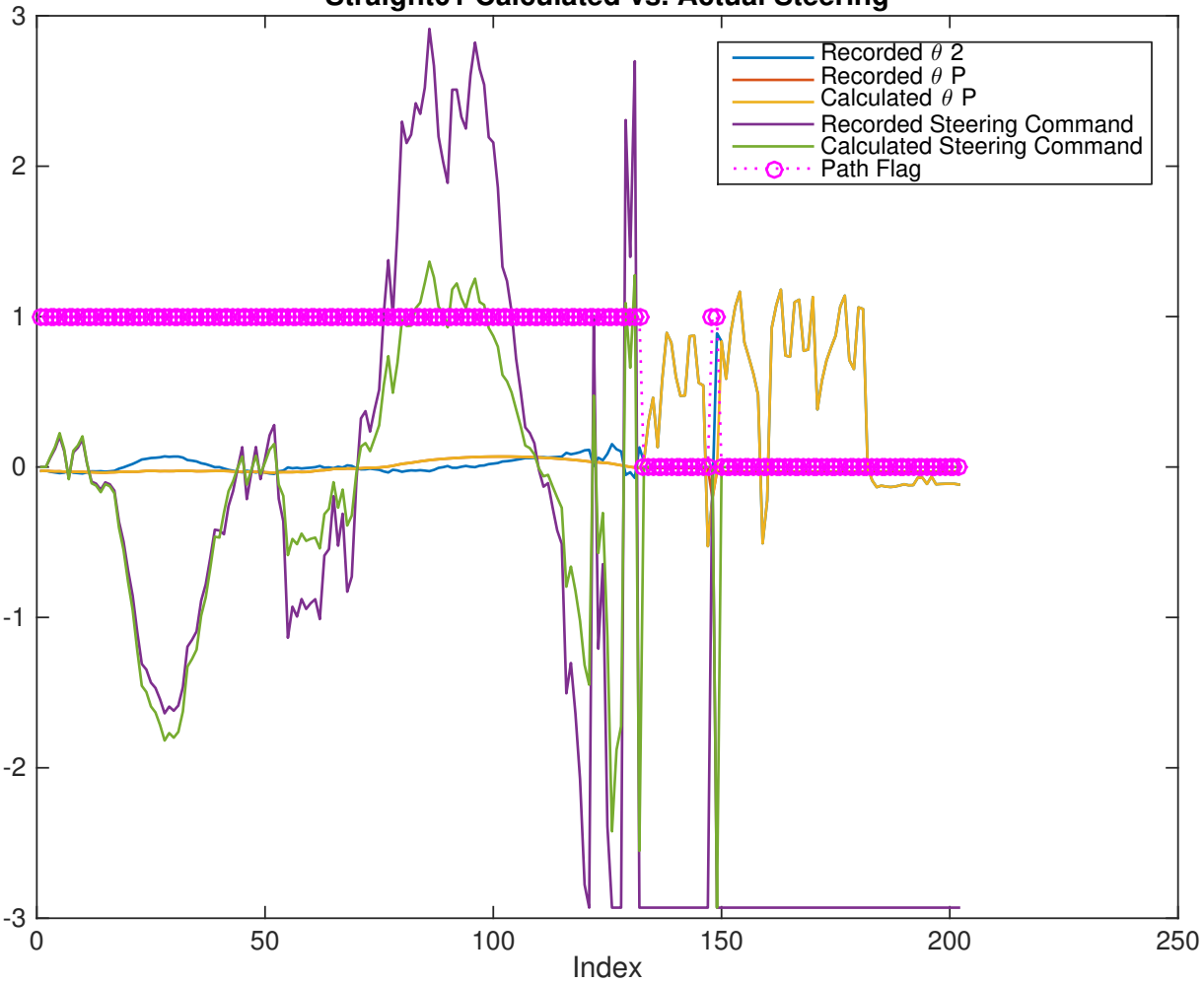
Straight01 Camera Position



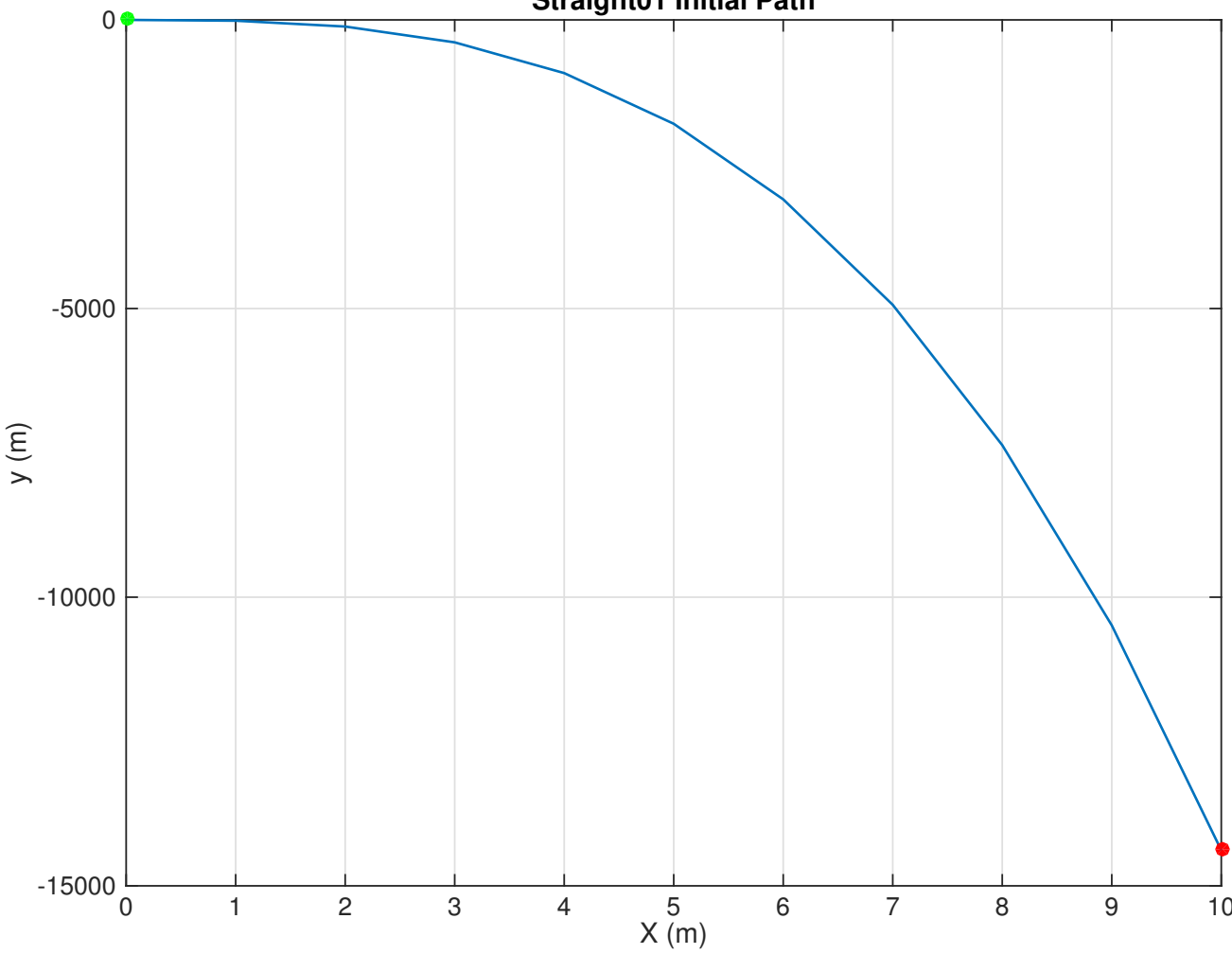
Straight01 Steering Command



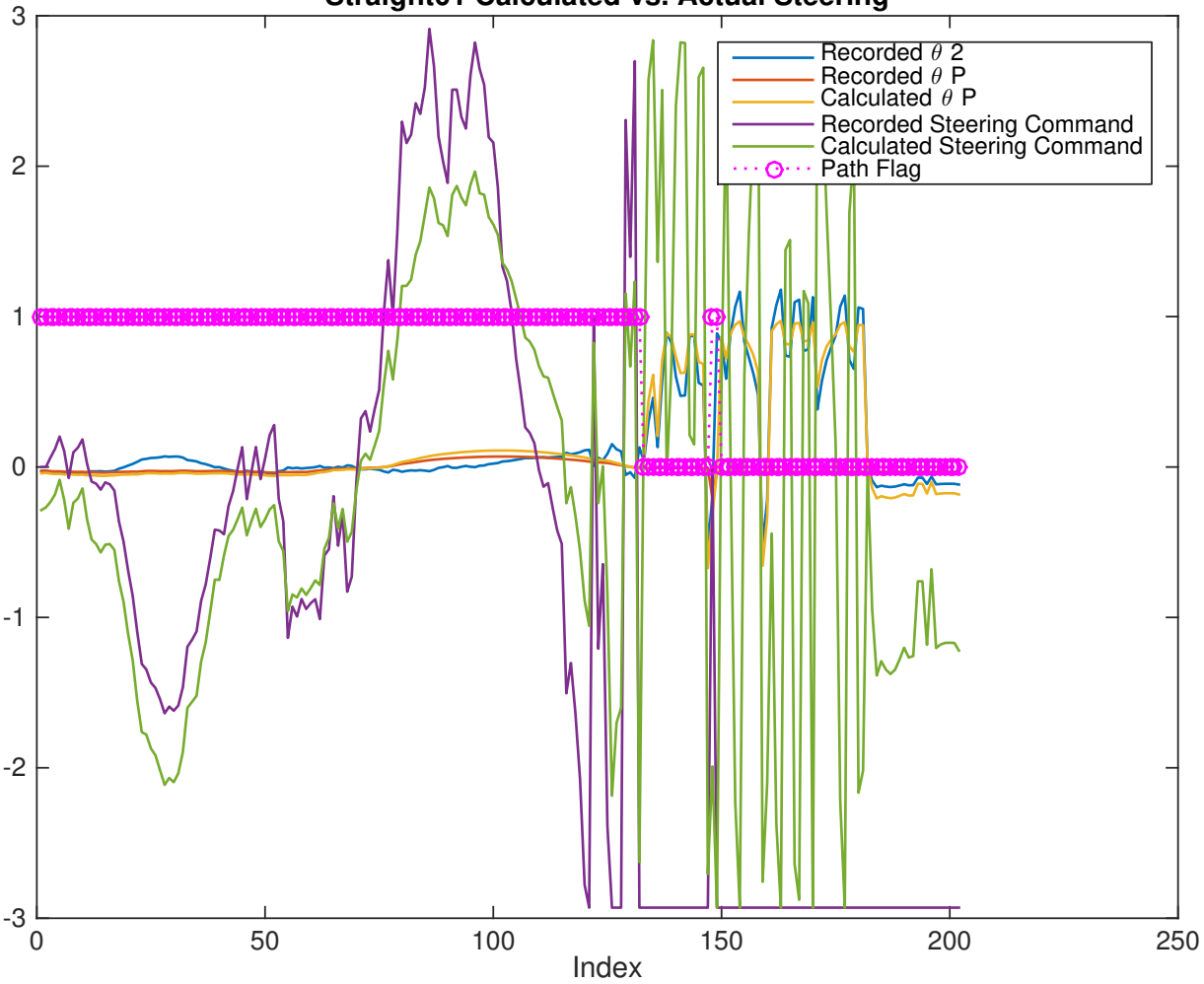
Straight01 Calculated vs. Actual Steering



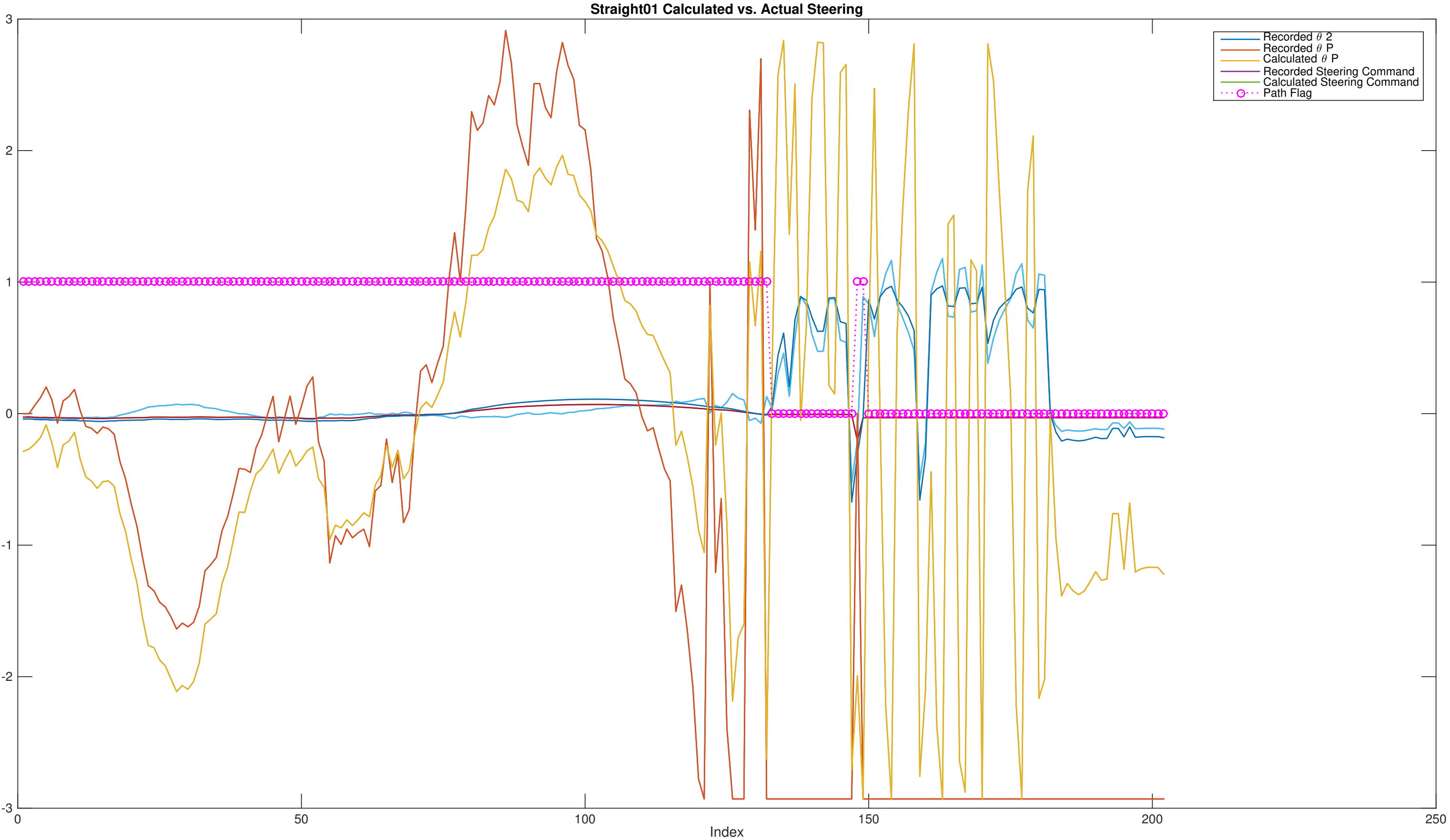
Straight01 Initial Path



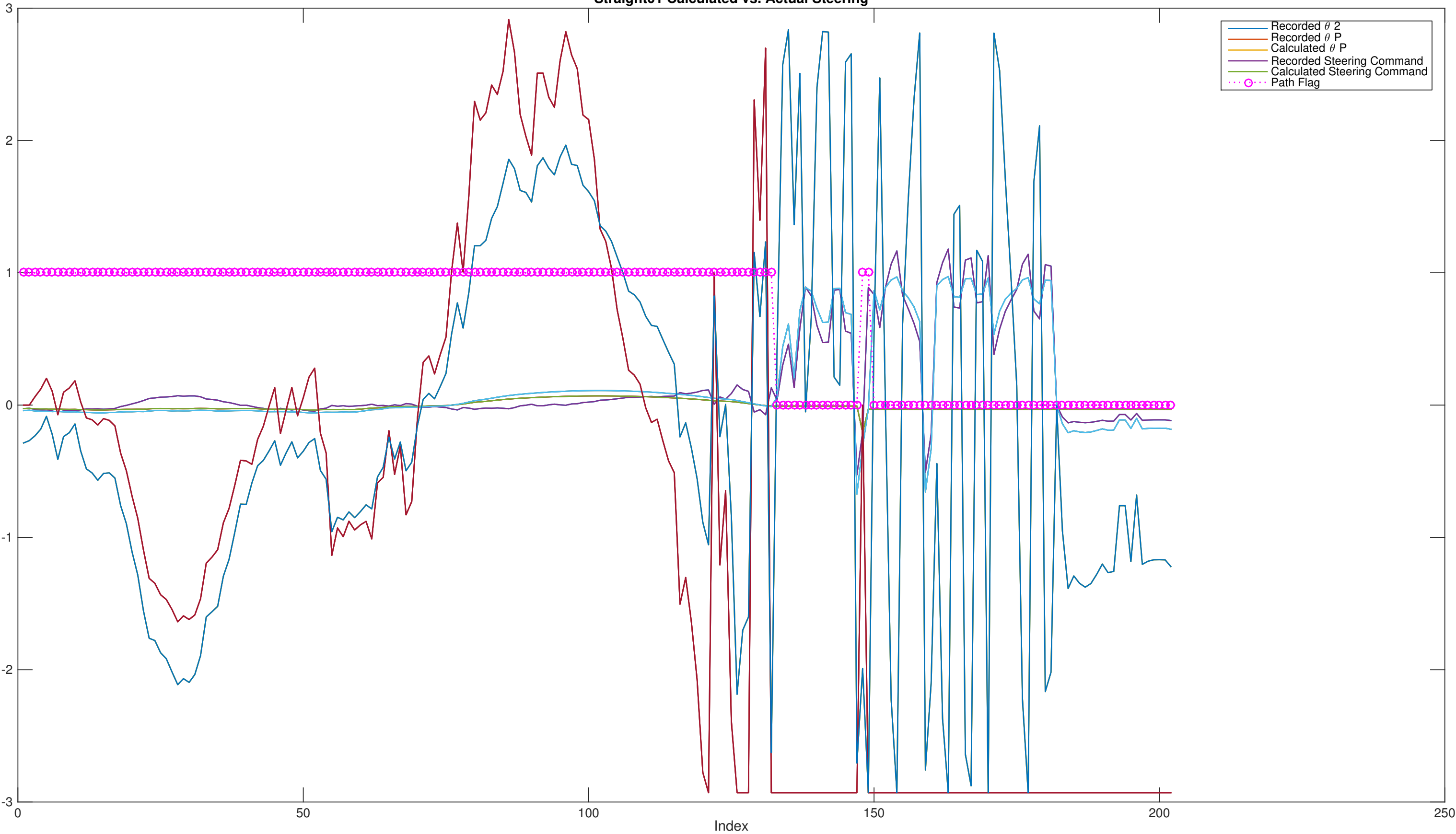
Straight01 Calculated vs. Actual Steering



Straight01 Calculated vs. Actual Steering



Straight01 Calculated vs. Actual Steering



Straight01 Calculated vs. Actual Steering

