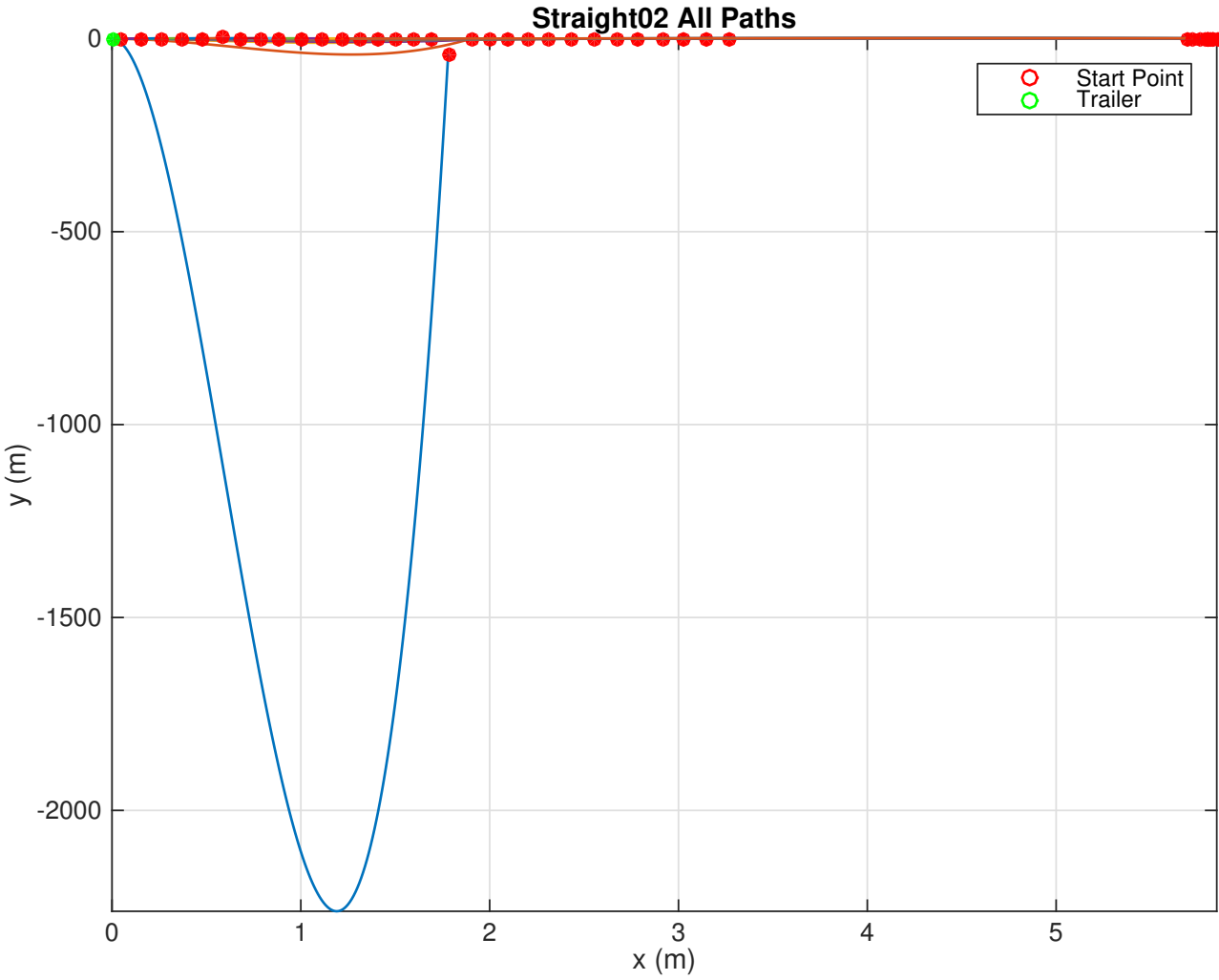


Straight02 All Paths



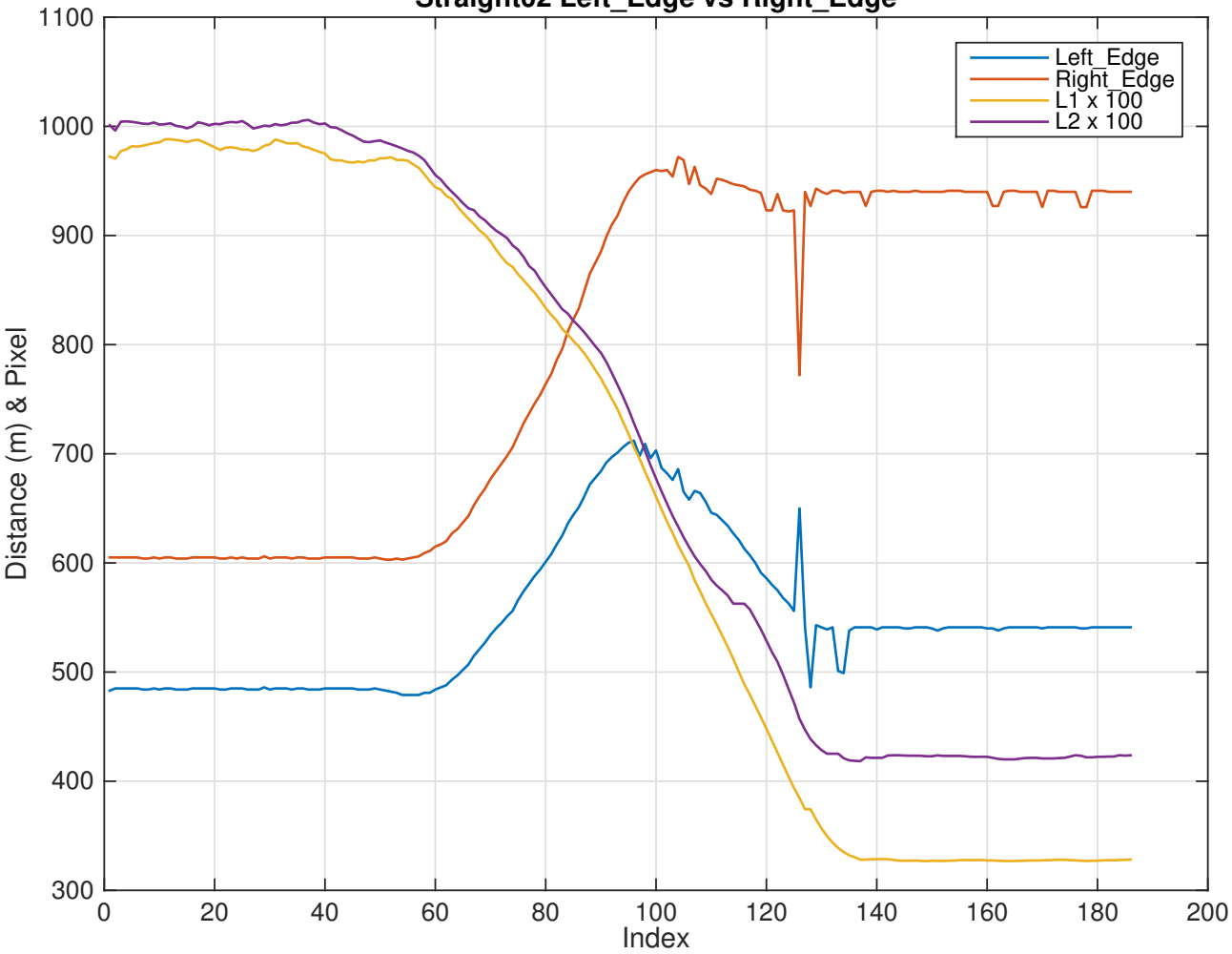
Number_Of_Unique_Paths

King_Pin_Detected

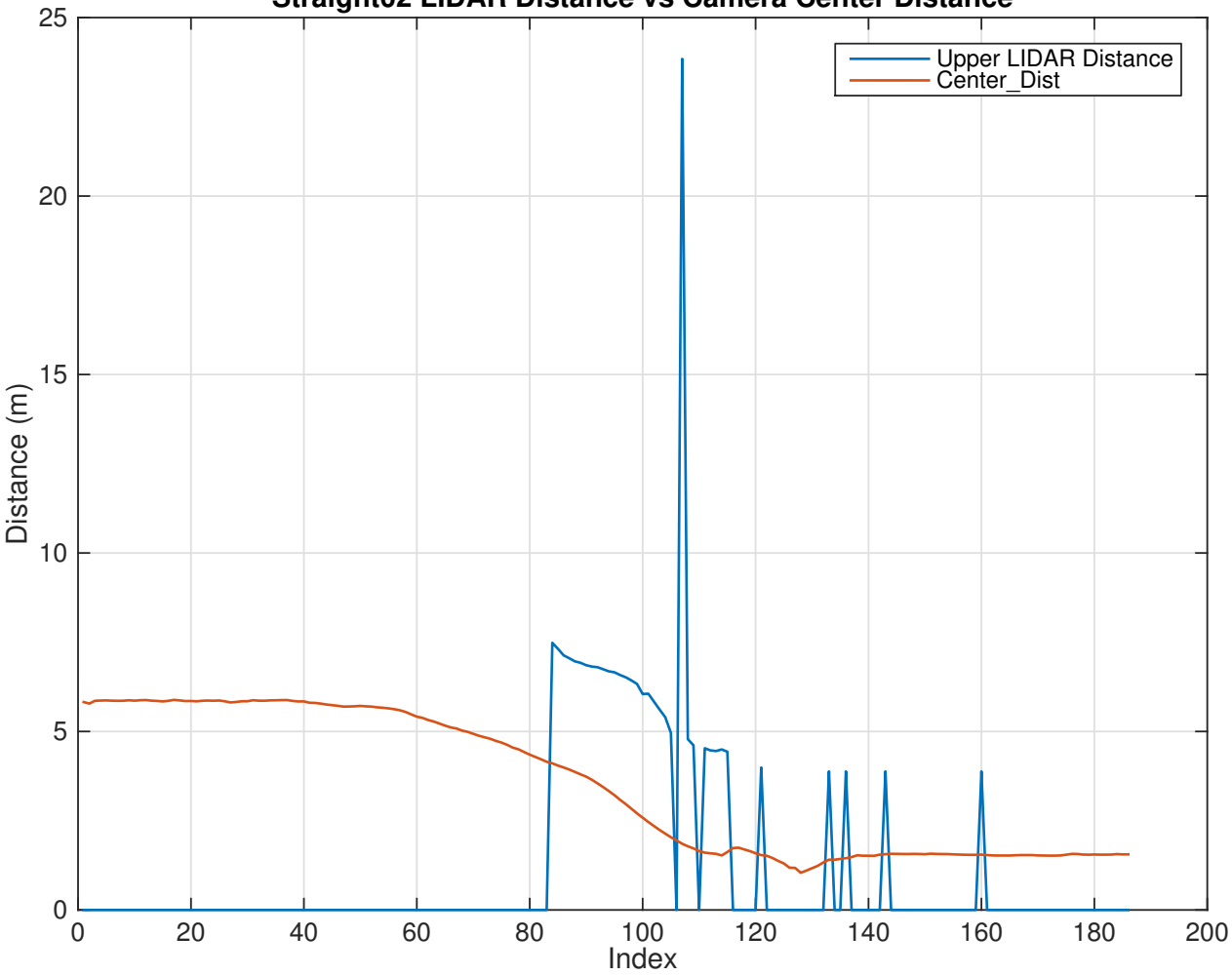
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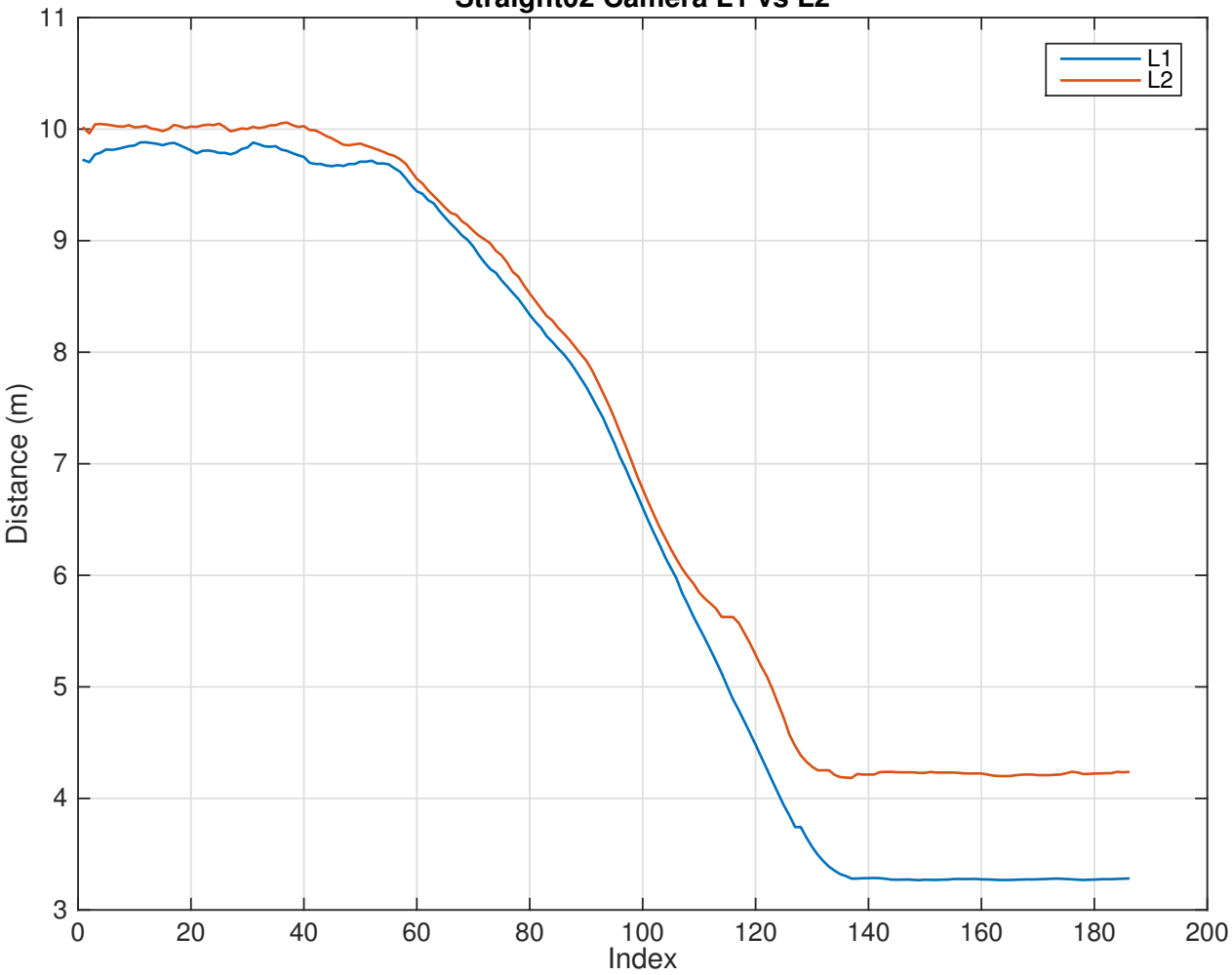
Straight02 Left_Edge vs Right_Edge



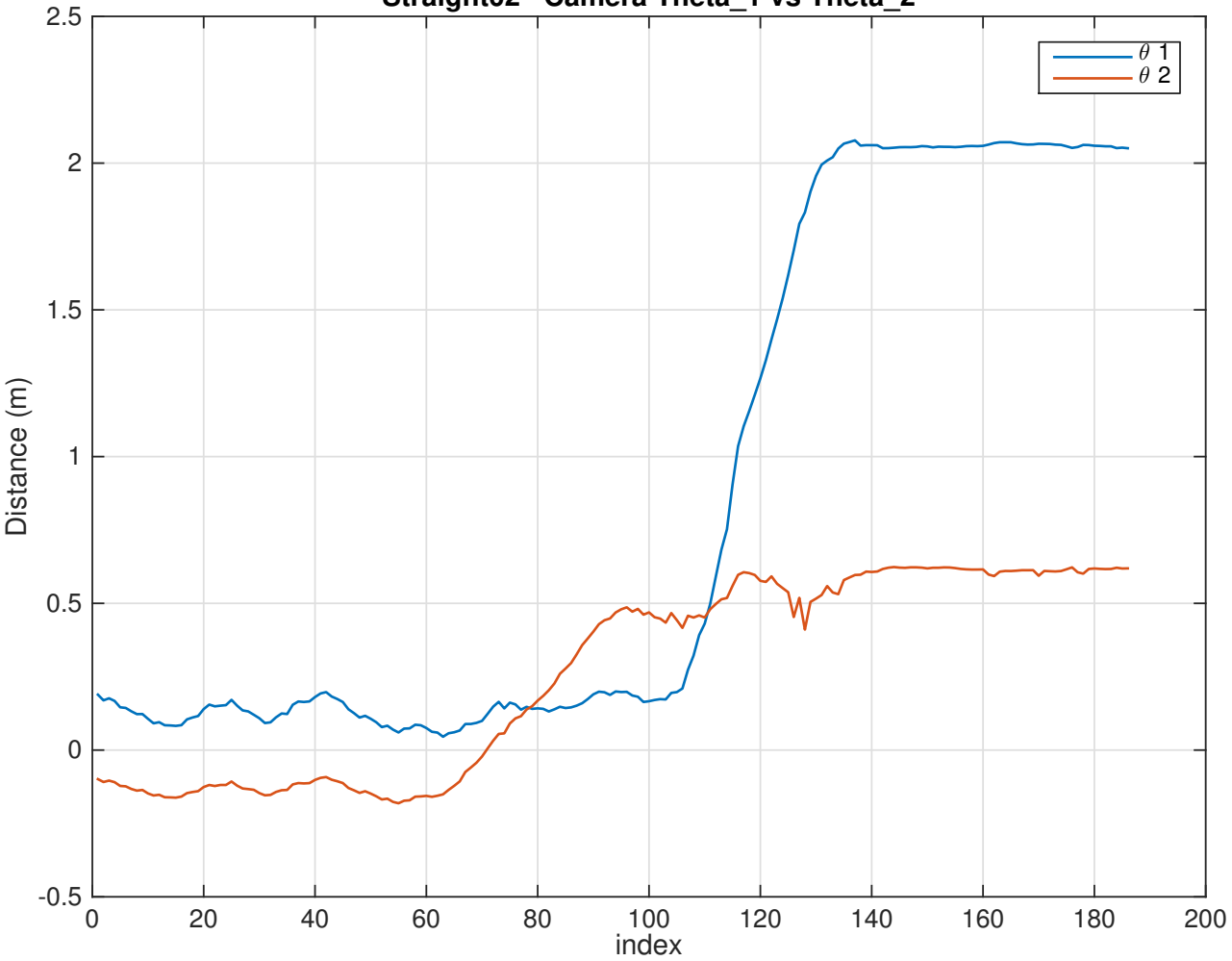
Straight02 LIDAR Distance vs Camera Center Distance



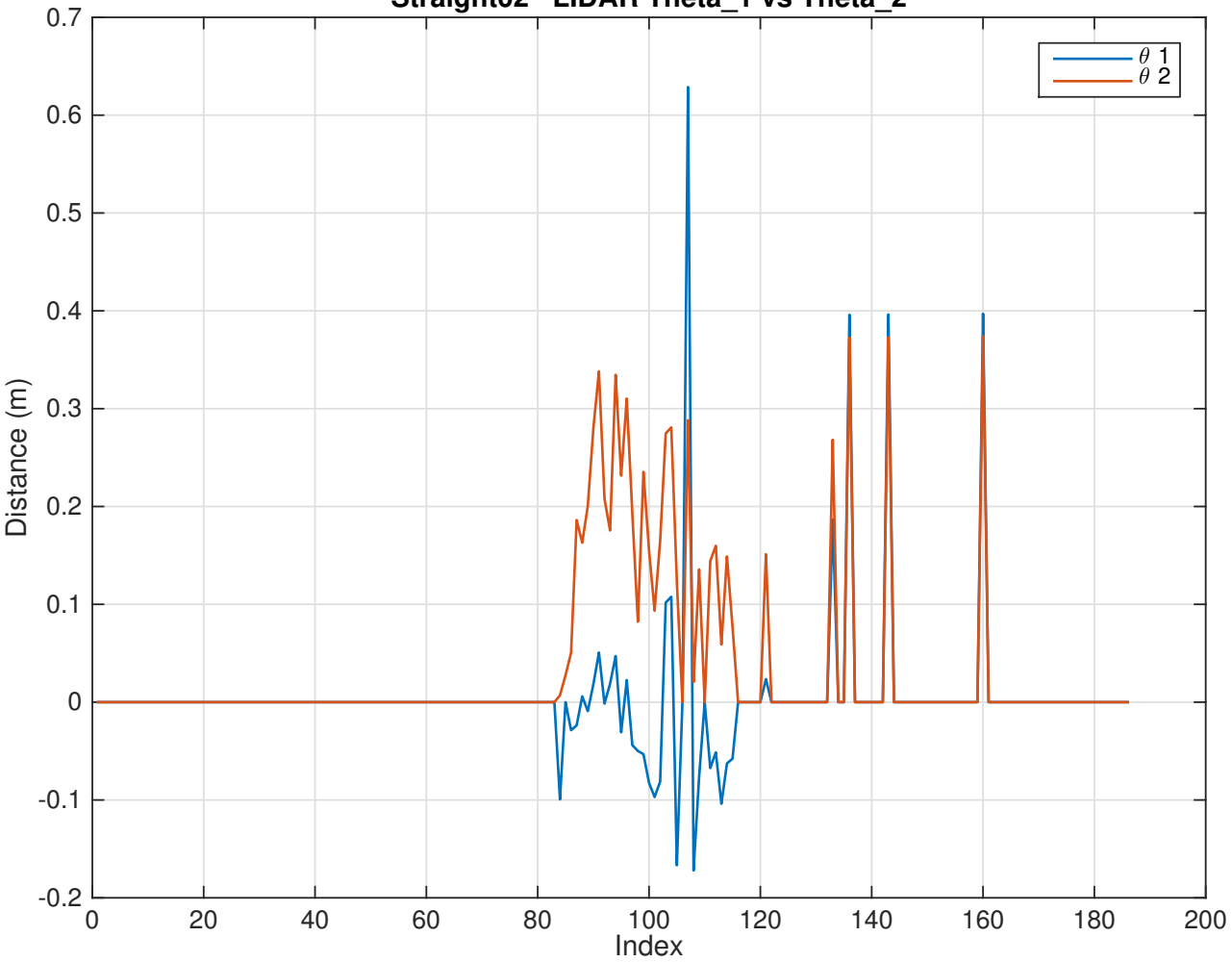
Straight02 Camera L1 vs L2



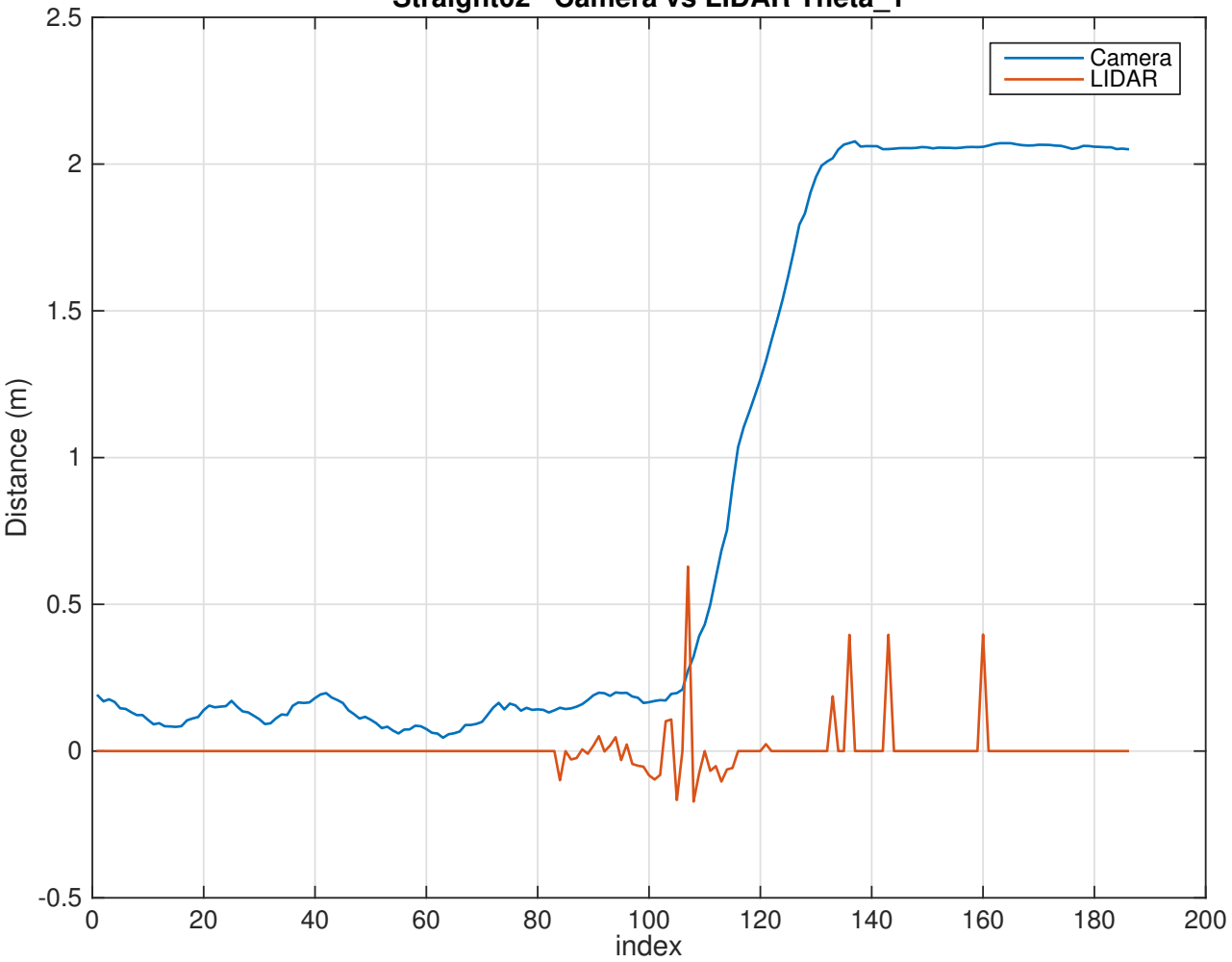
Straight02 Camera Theta_1 vs Theta_2



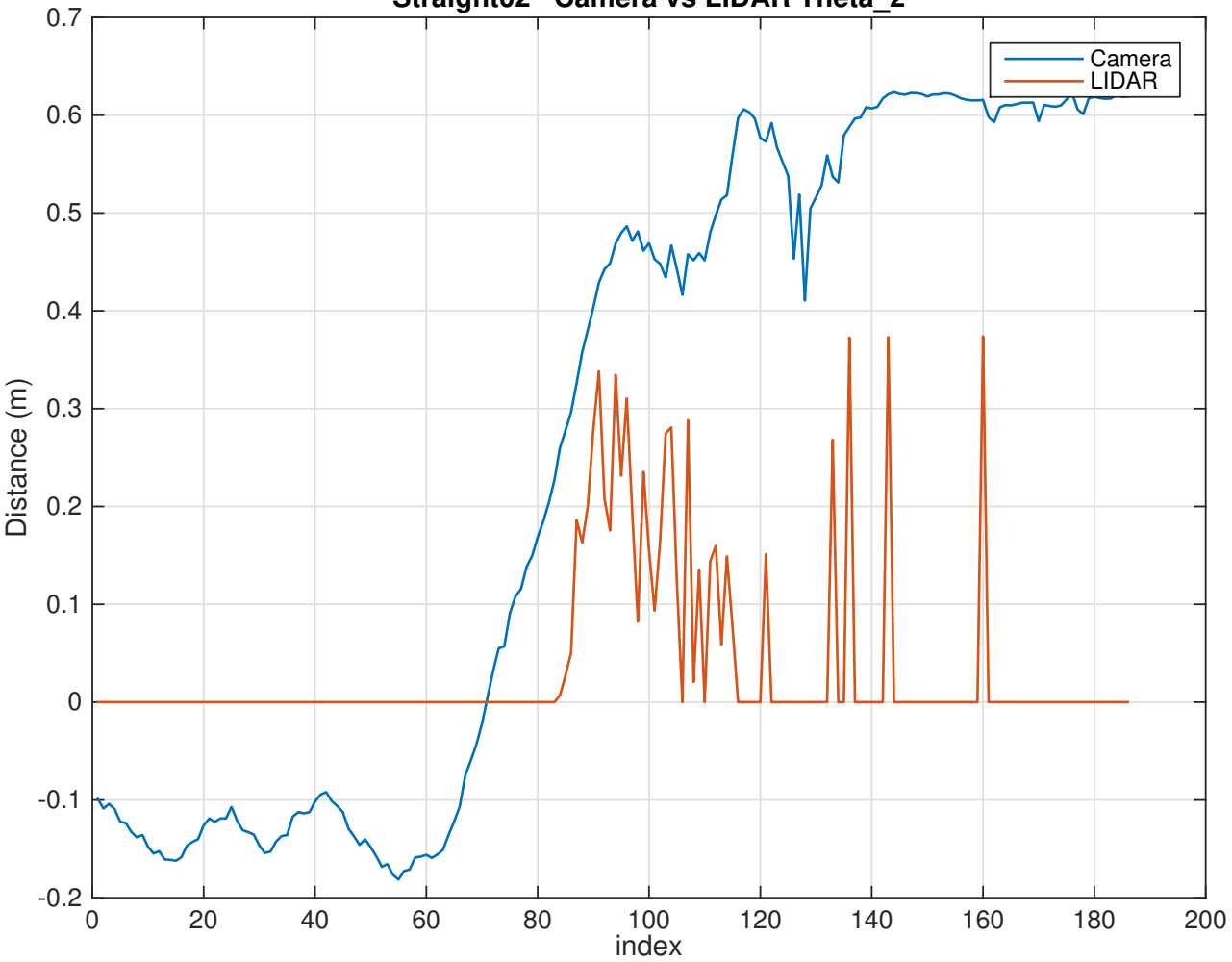
Straight02 LIDAR Theta_1 vs Theta_2



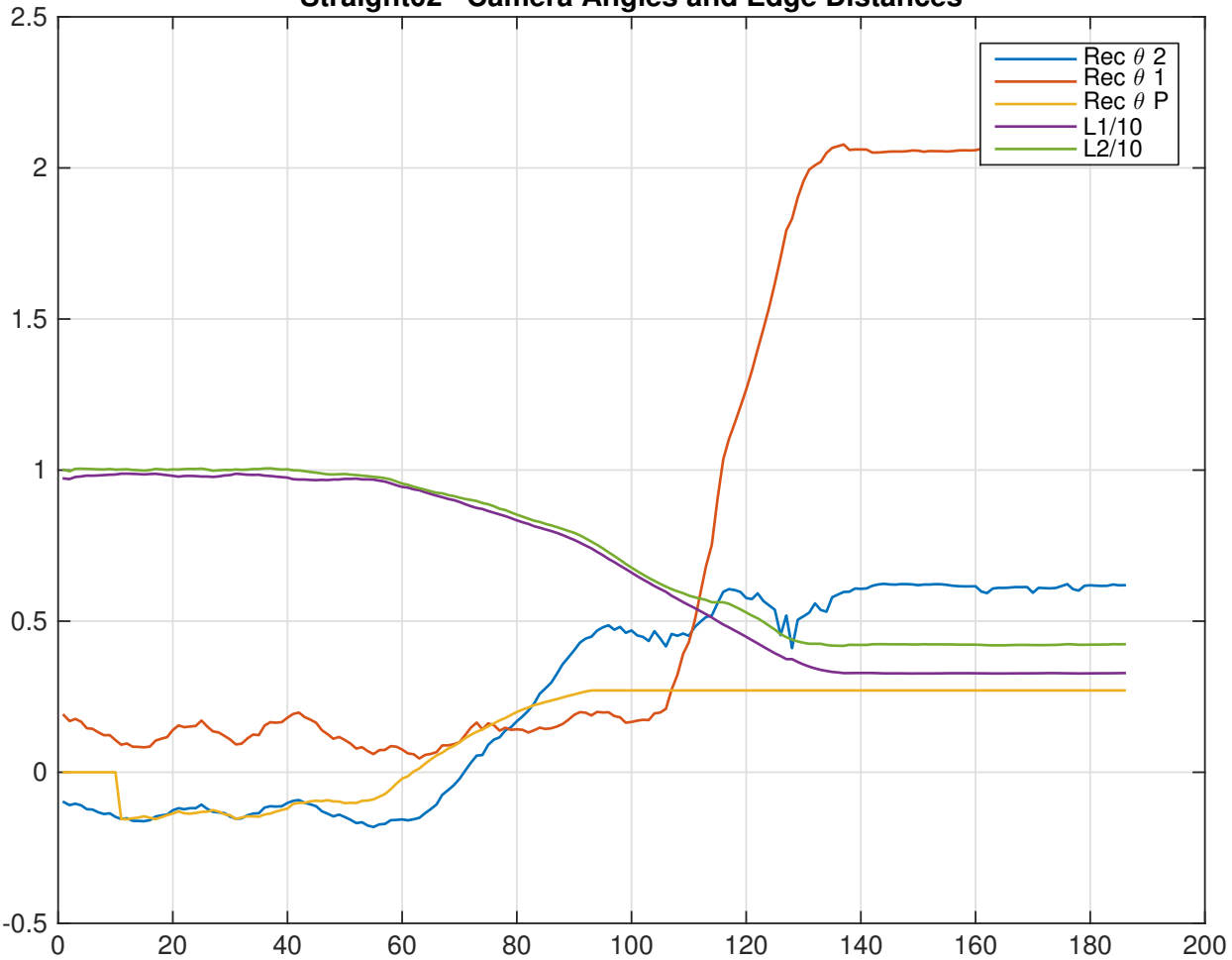
Straight02 Camera vs LIDAR Theta_1



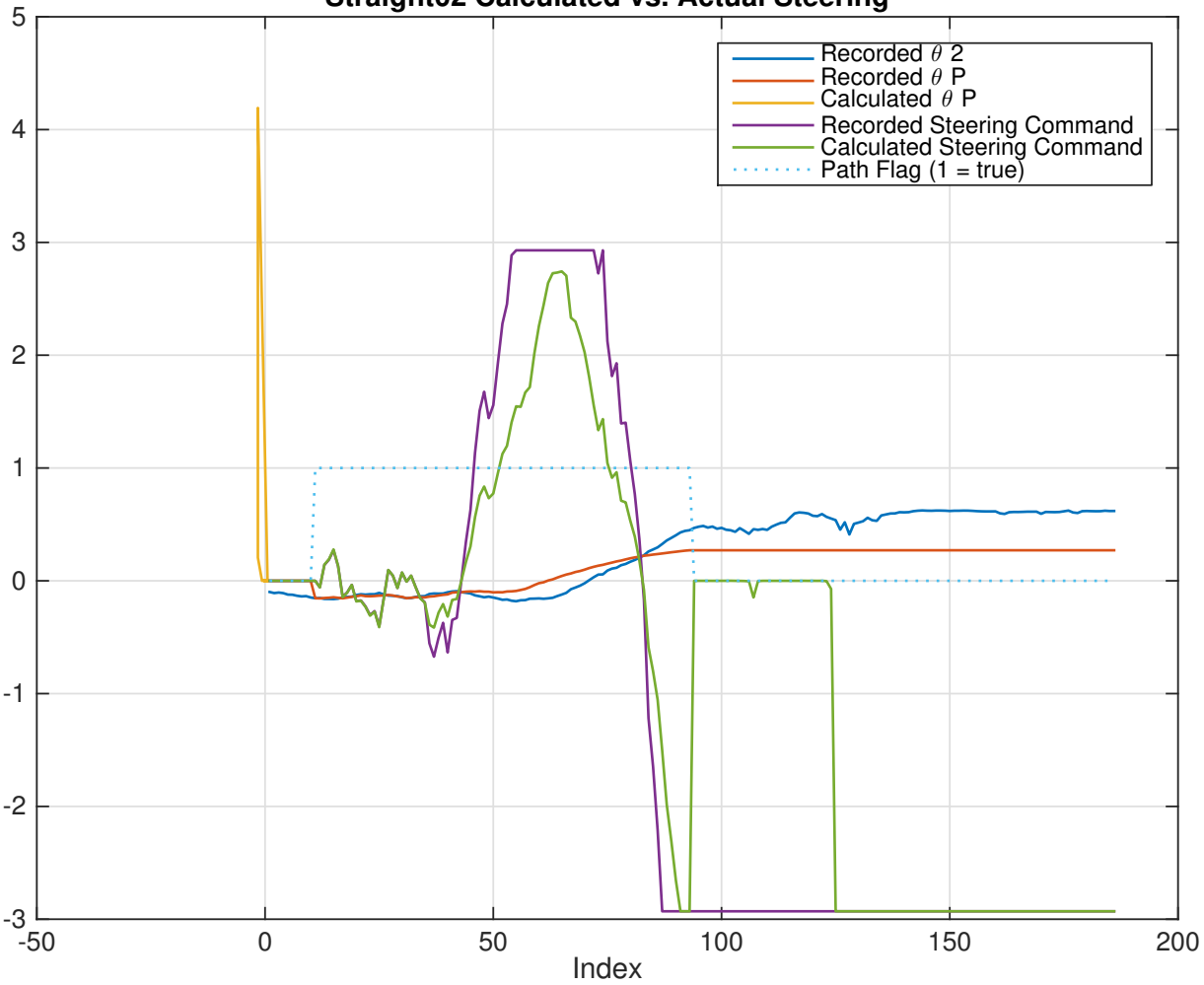
Straight02 Camera vs LIDAR Theta_2



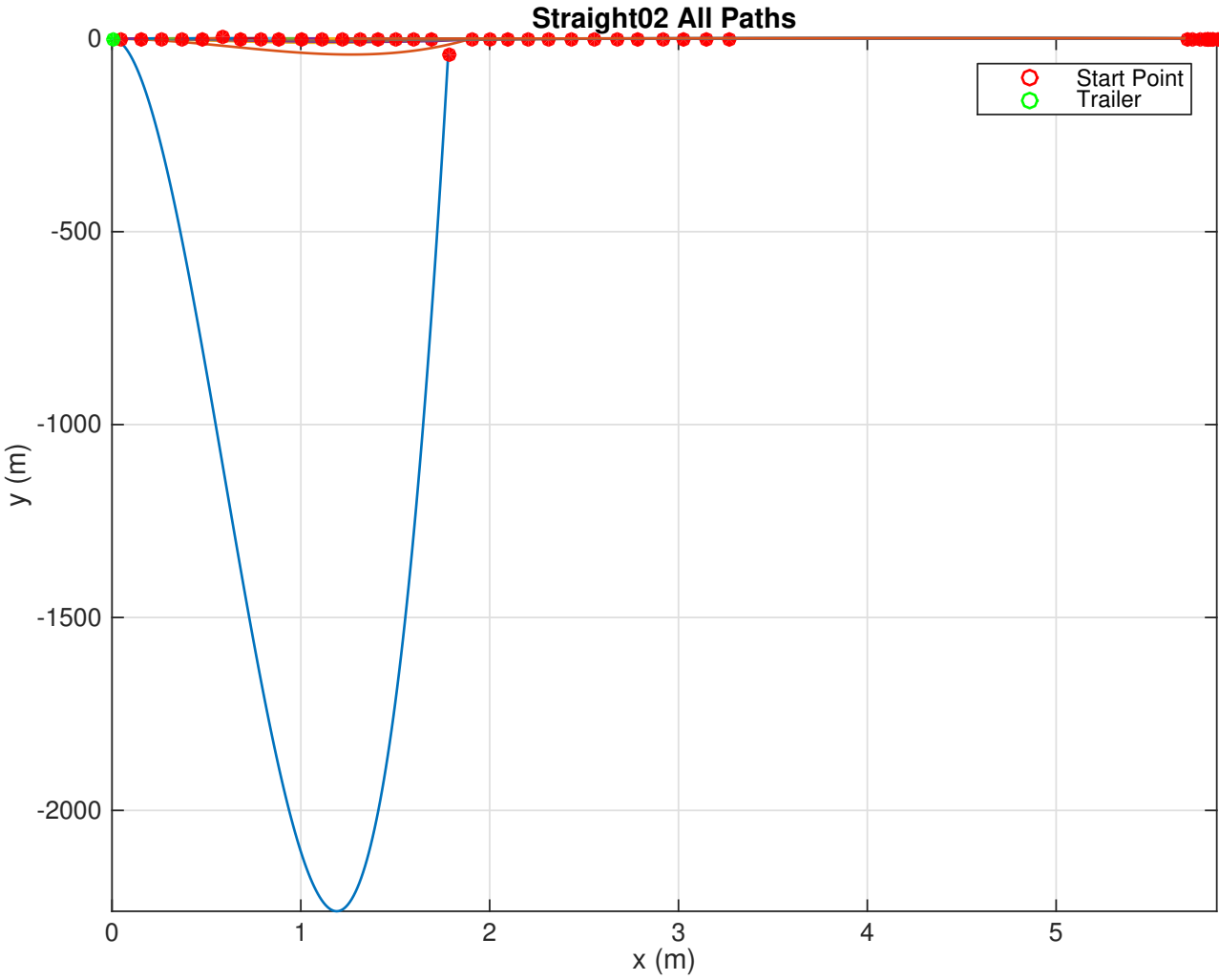
Straight02 Camera Angles and Edge Distances



Straight02 Calculated vs. Actual Steering



Straight02 All Paths



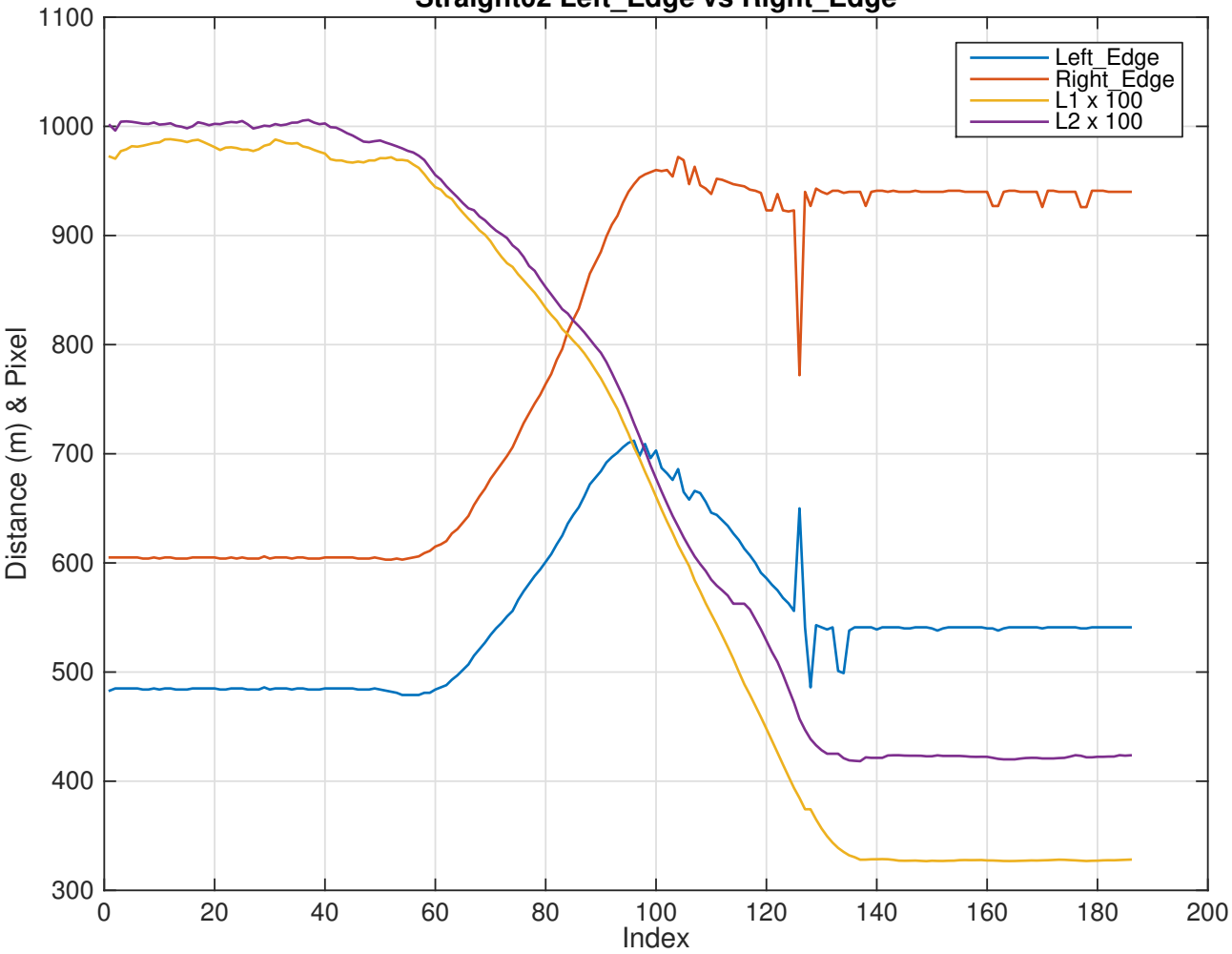
Number_Of_Unique_Paths

King_Pin_Detected

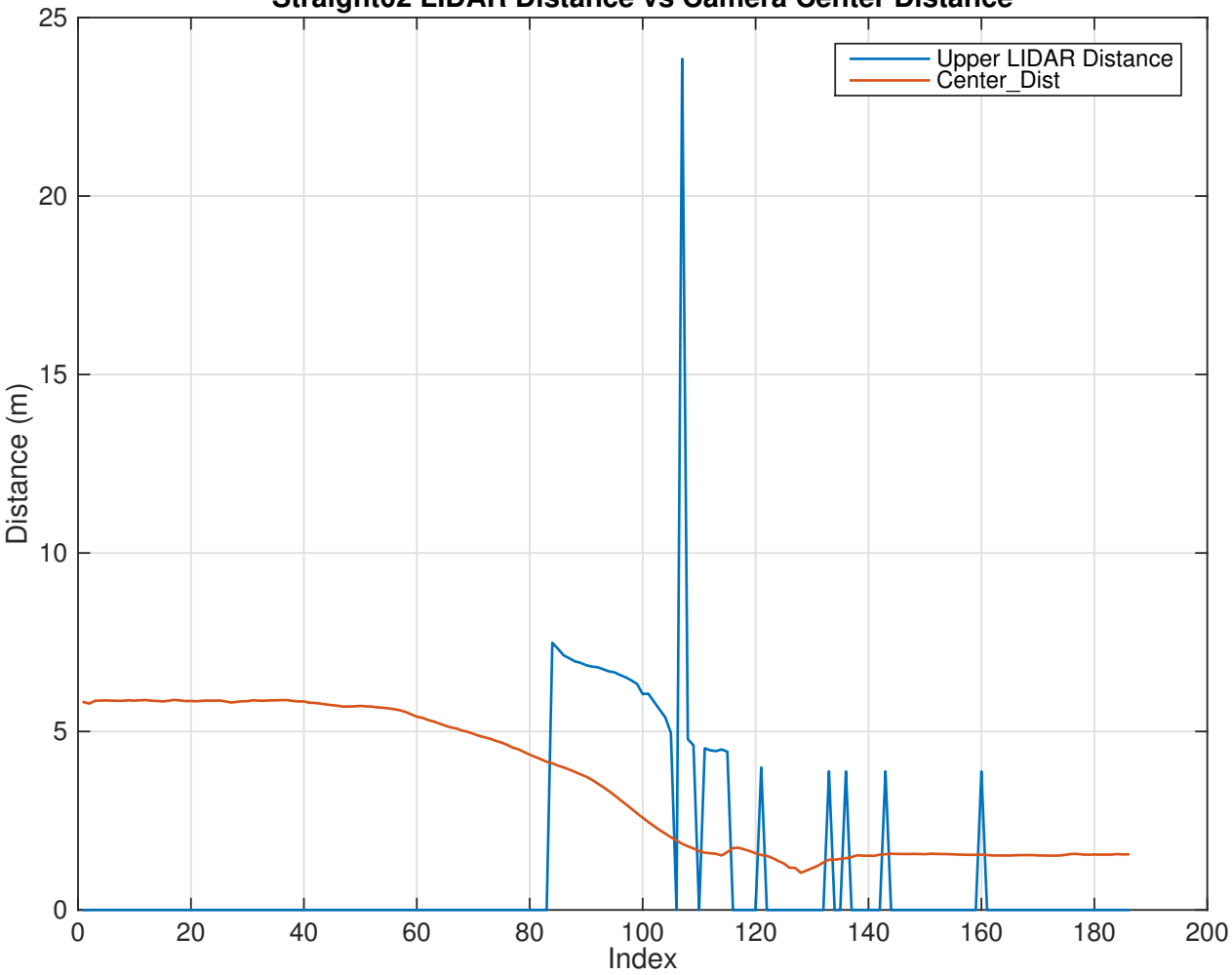
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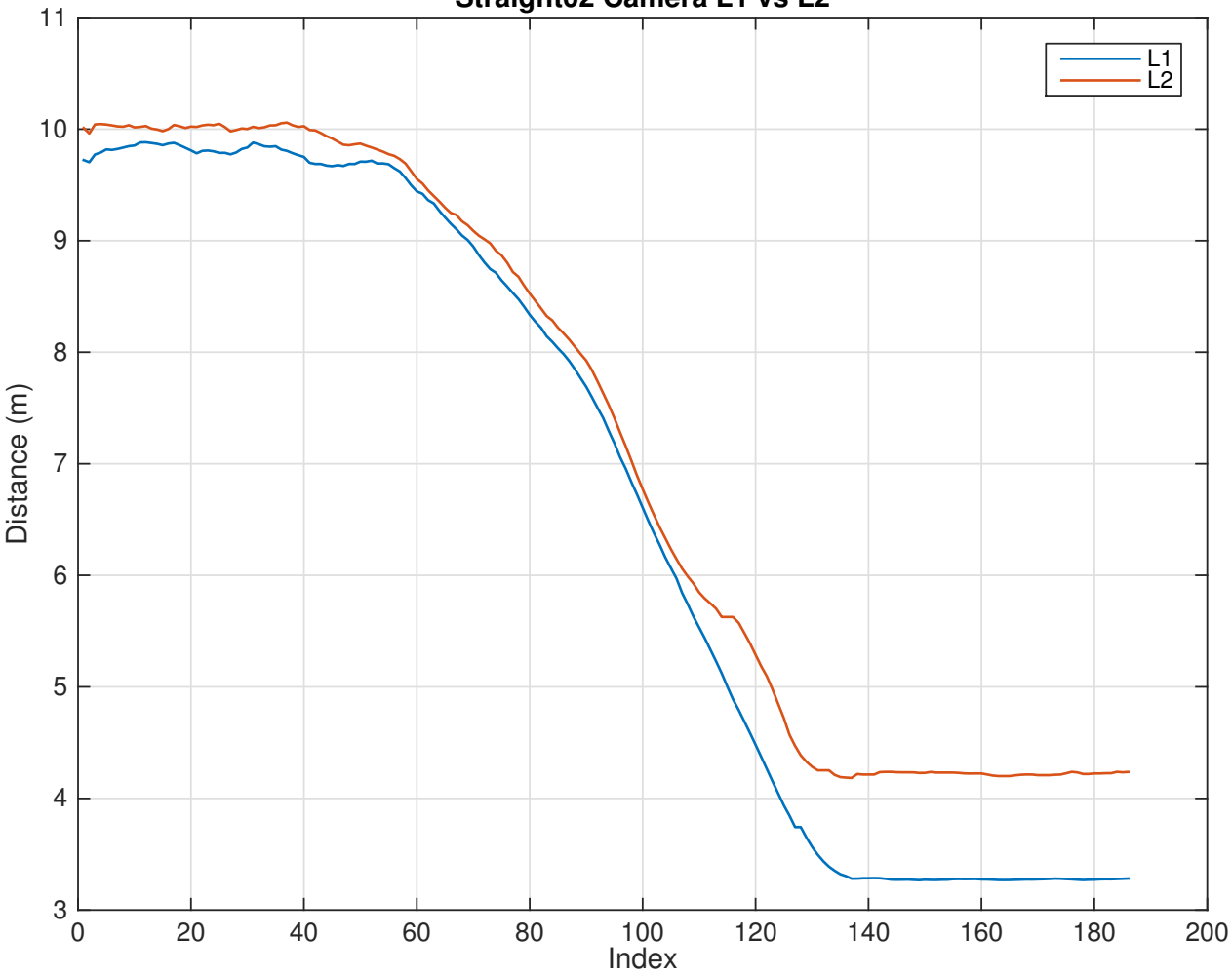
Straight02 Left_Edge vs Right_Edge



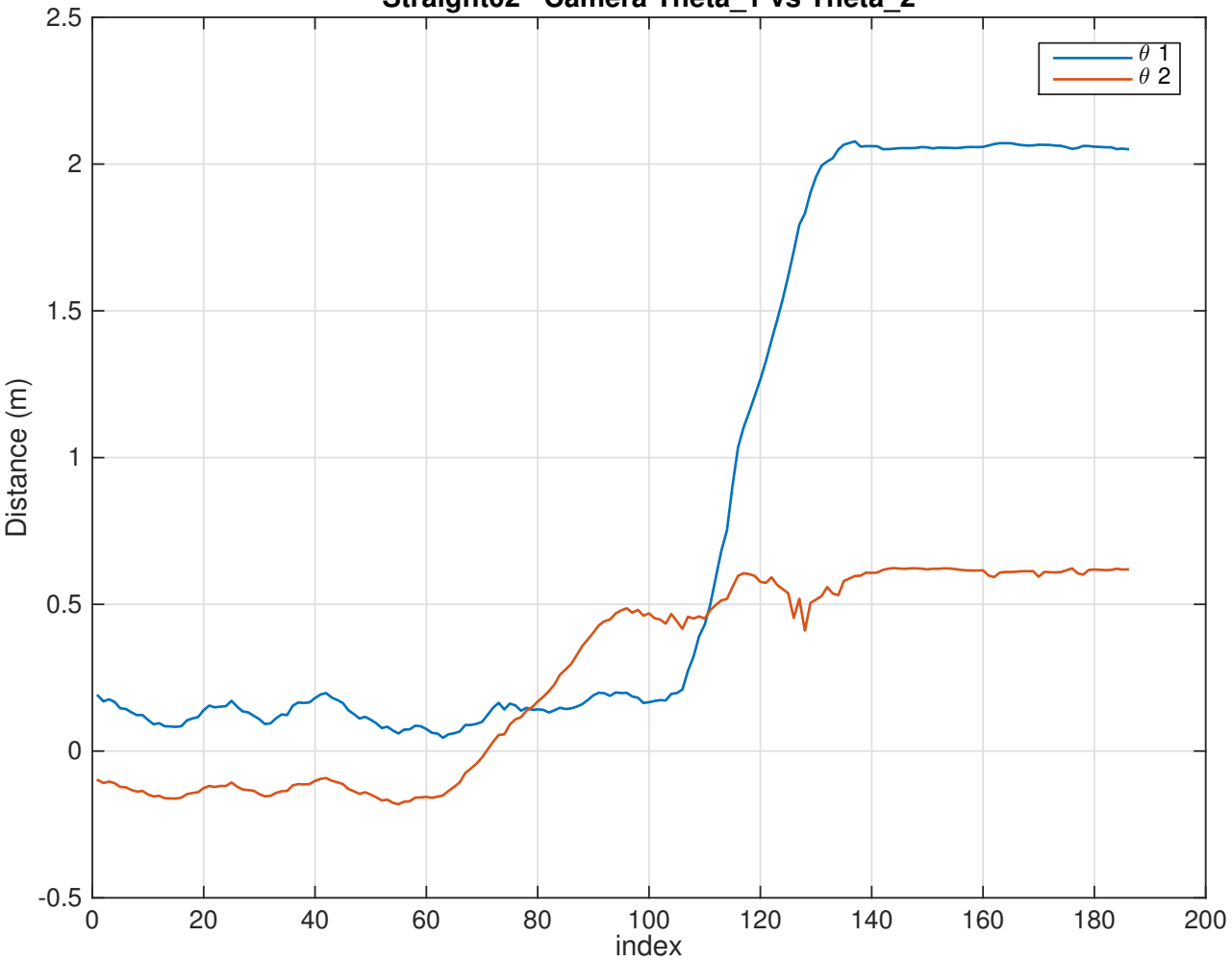
Straight02 LIDAR Distance vs Camera Center Distance



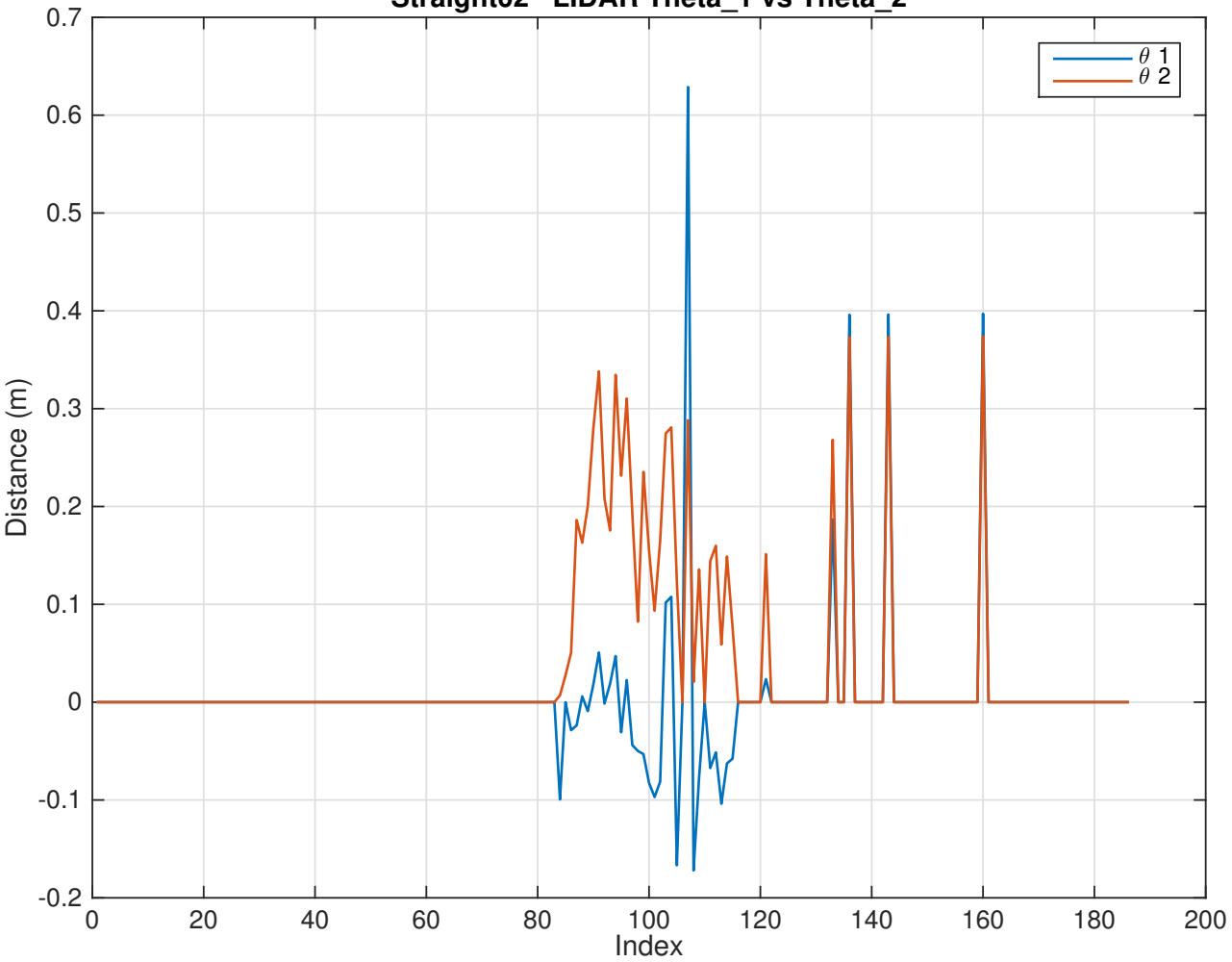
Straight02 Camera L1 vs L2



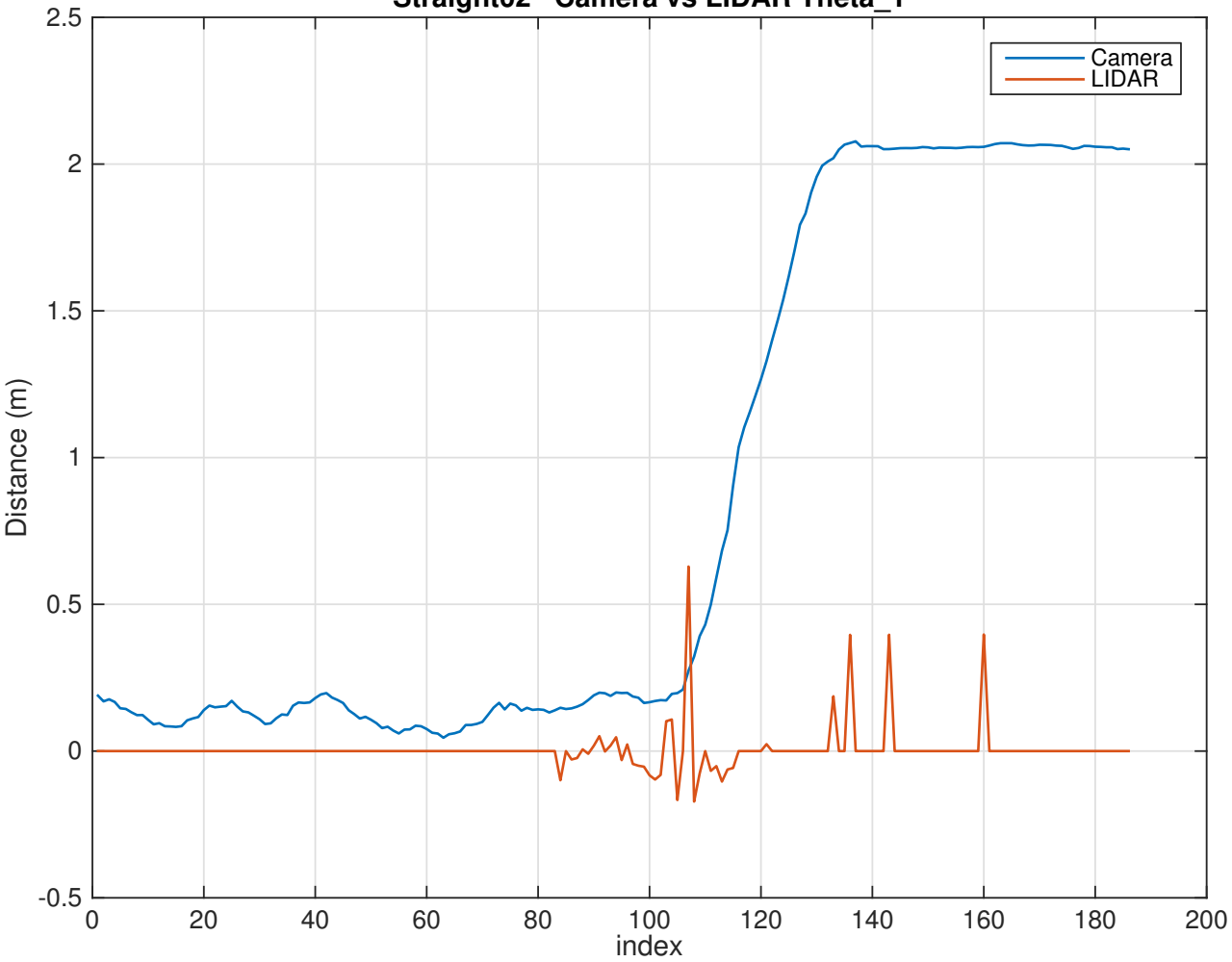
Straight02 Camera Theta_1 vs Theta_2



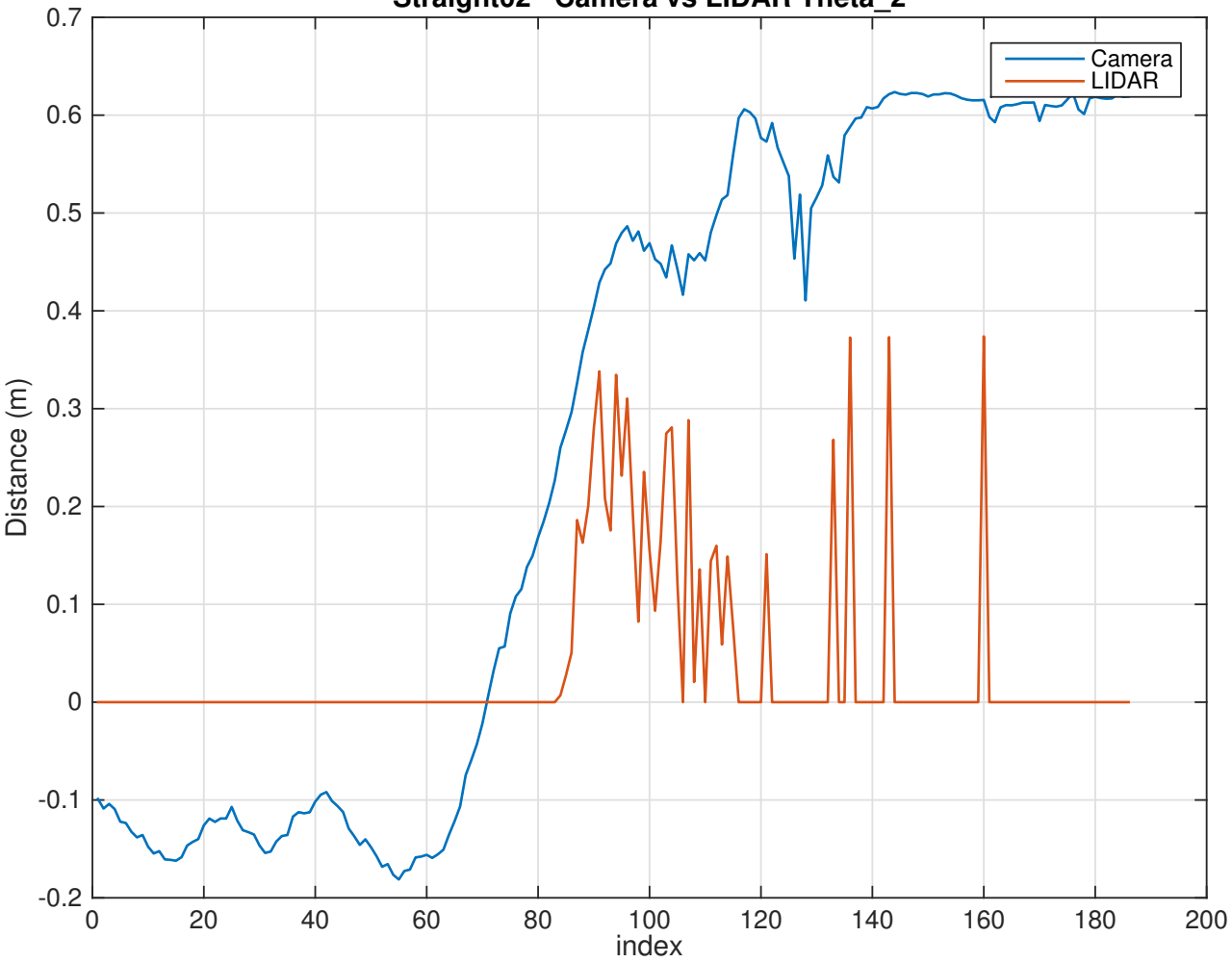
Straight02 LIDAR Theta_1 vs Theta_2



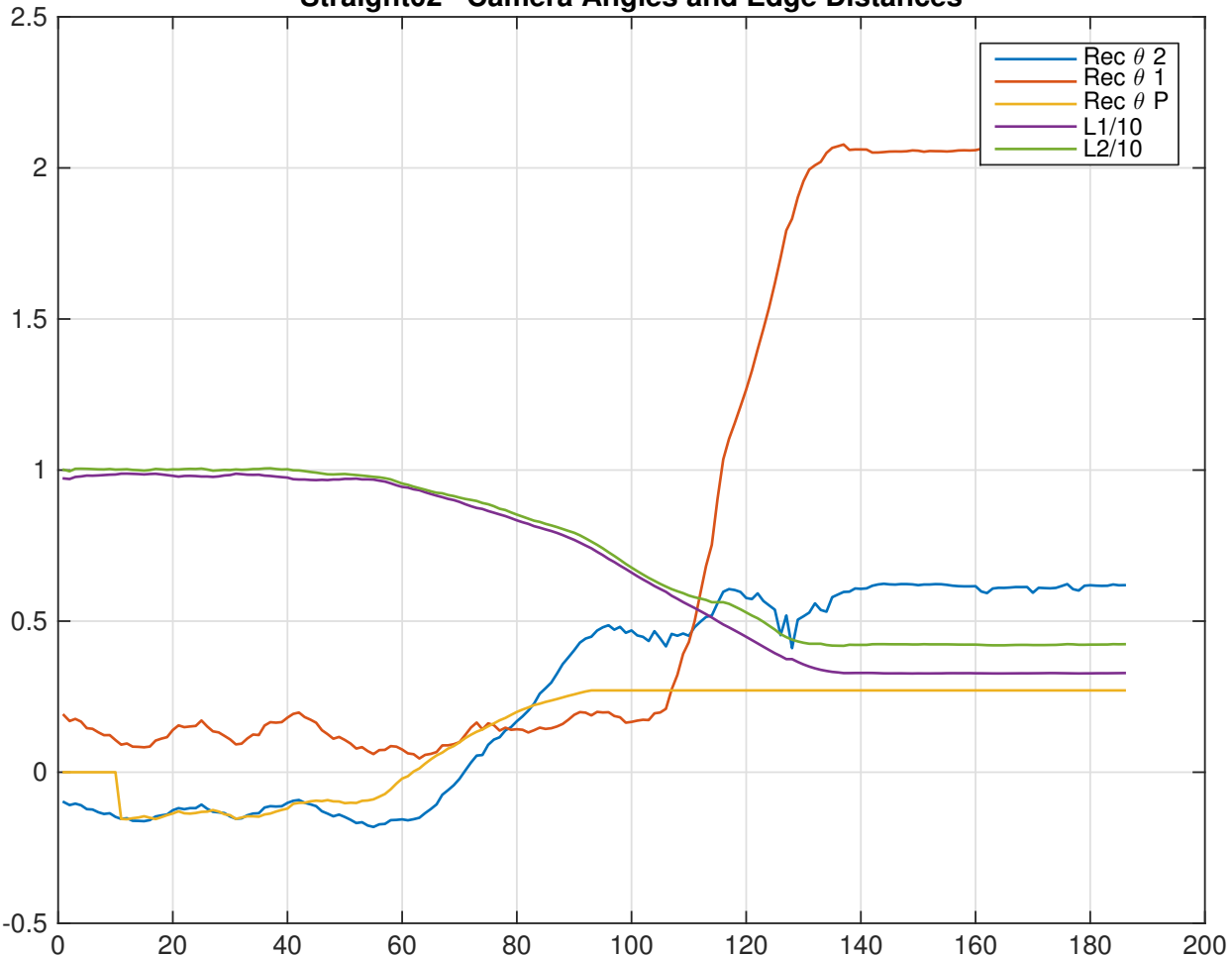
Straight02 Camera vs LIDAR Theta_1



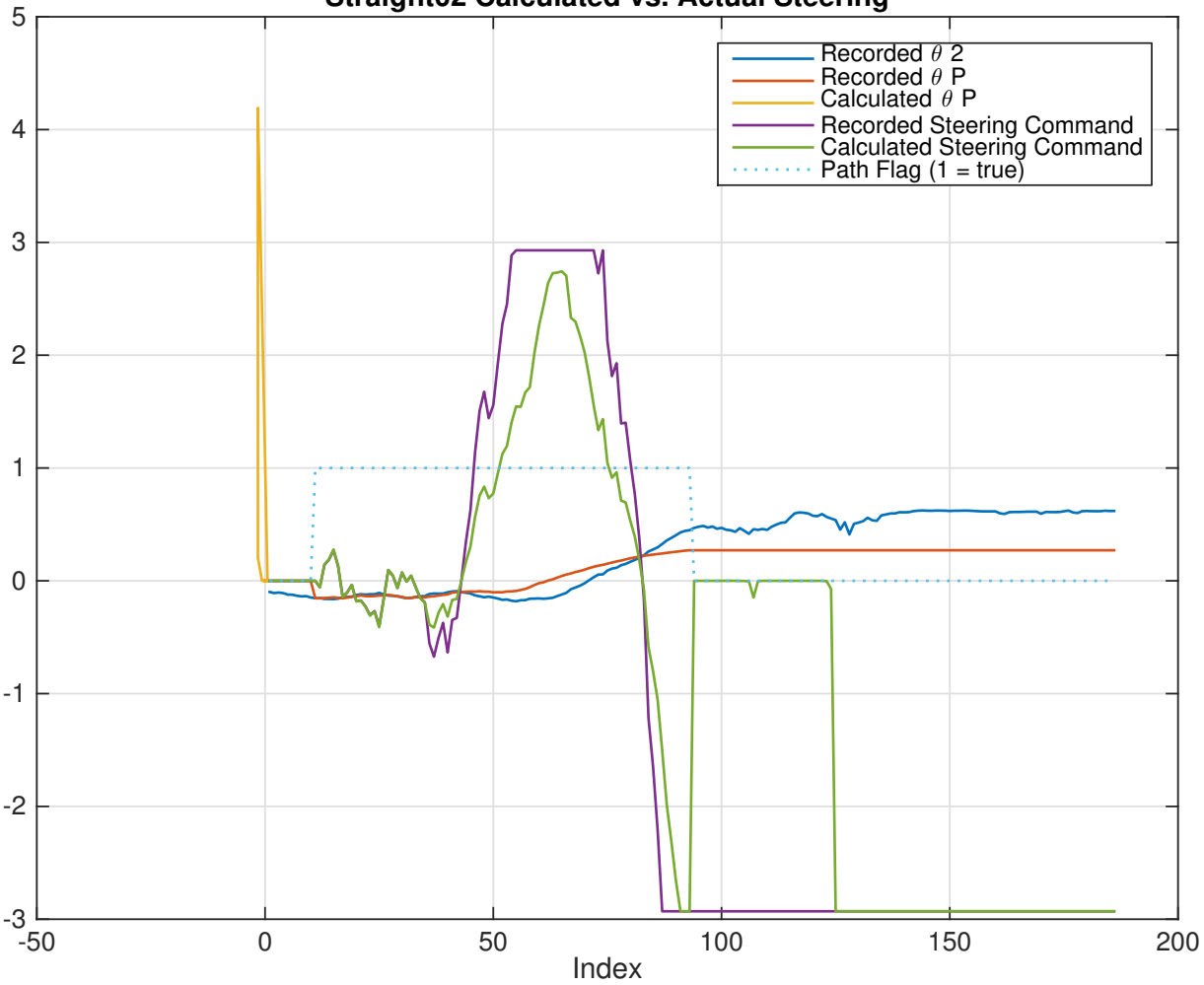
Straight02 Camera vs LIDAR Theta_2



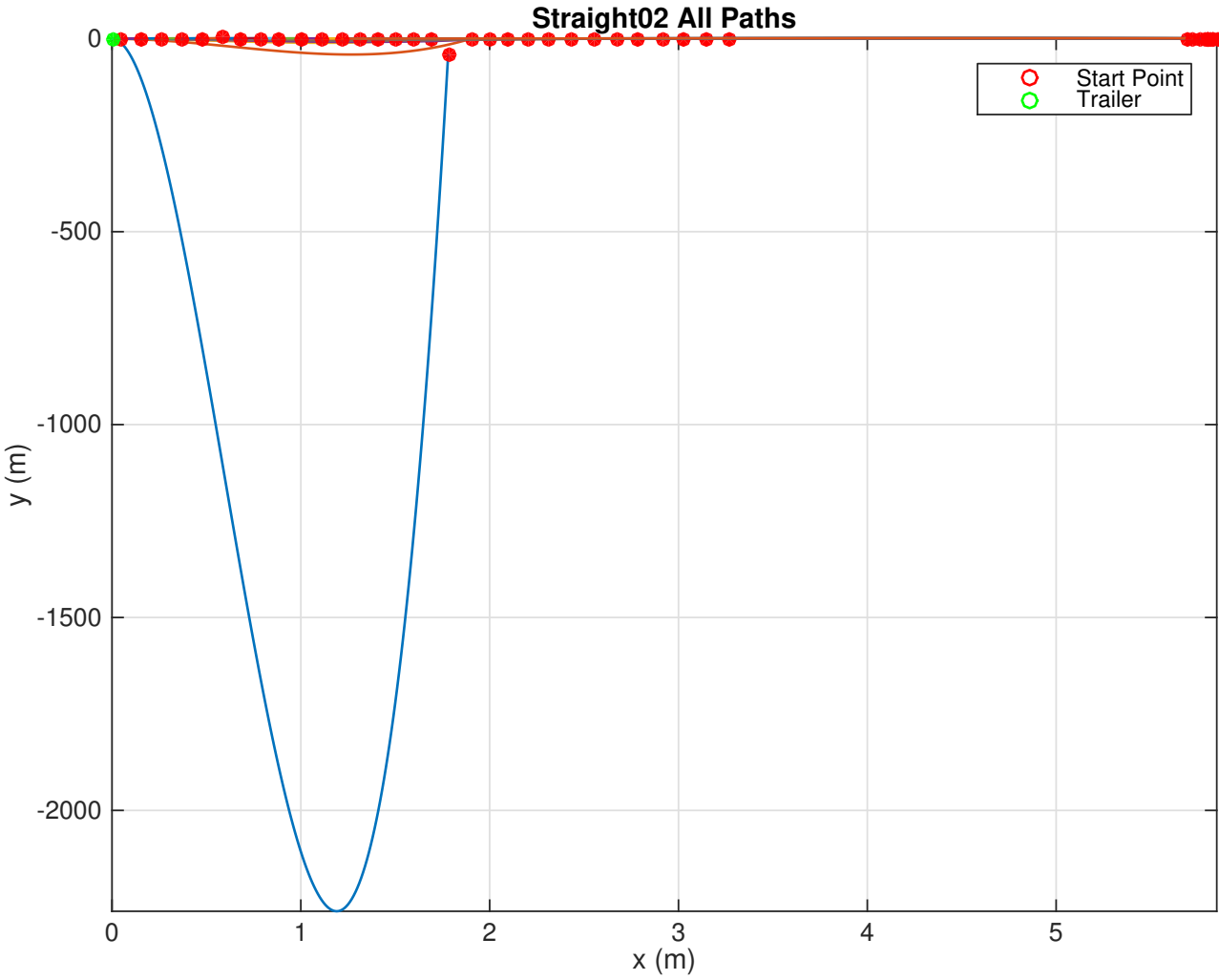
Straight02 Camera Angles and Edge Distances



Straight02 Calculated vs. Actual Steering



Straight02 All Paths



Number_Of_Unique_Paths

King_Pin_Detected

23

false