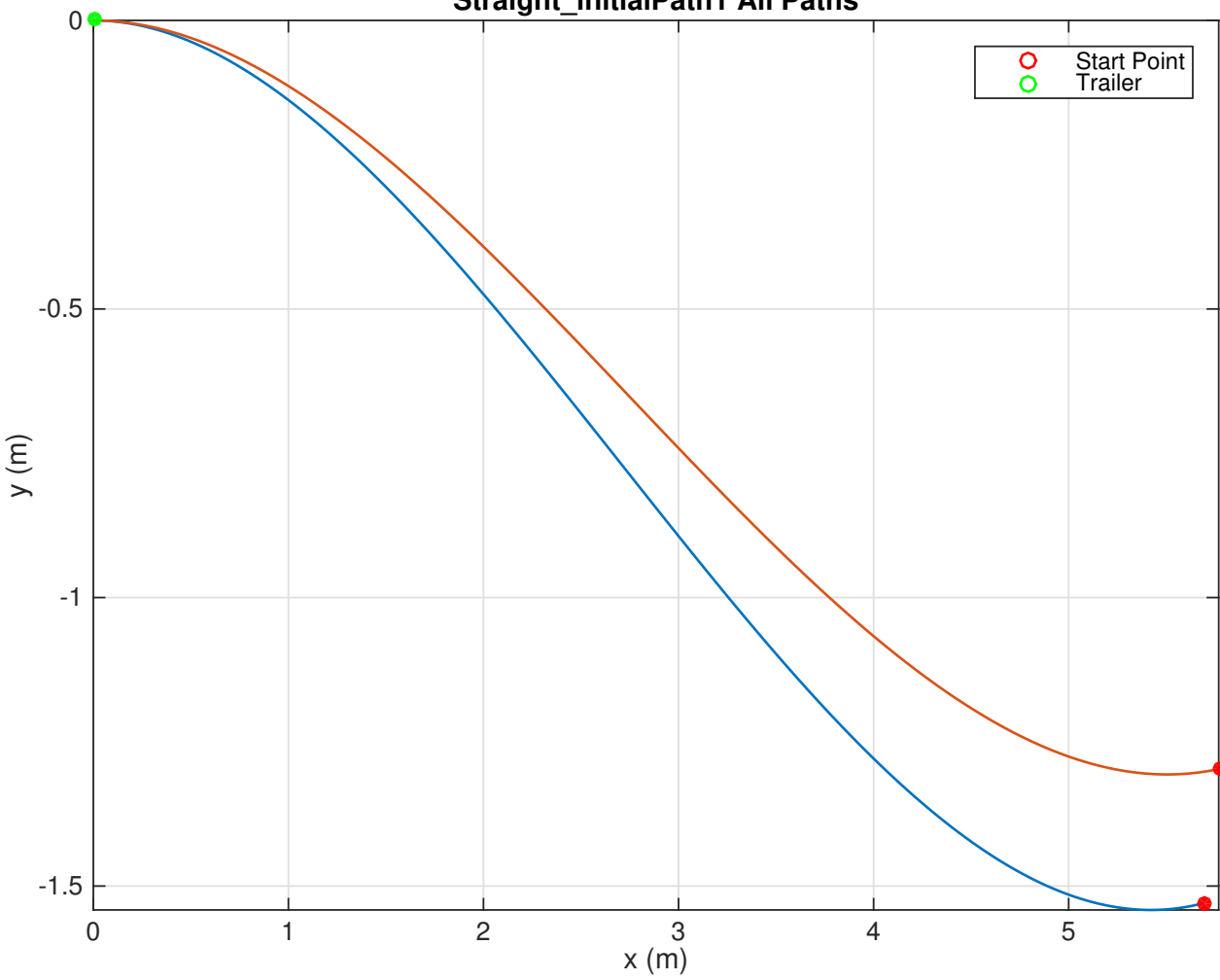


Straight_initialPath1 All Paths



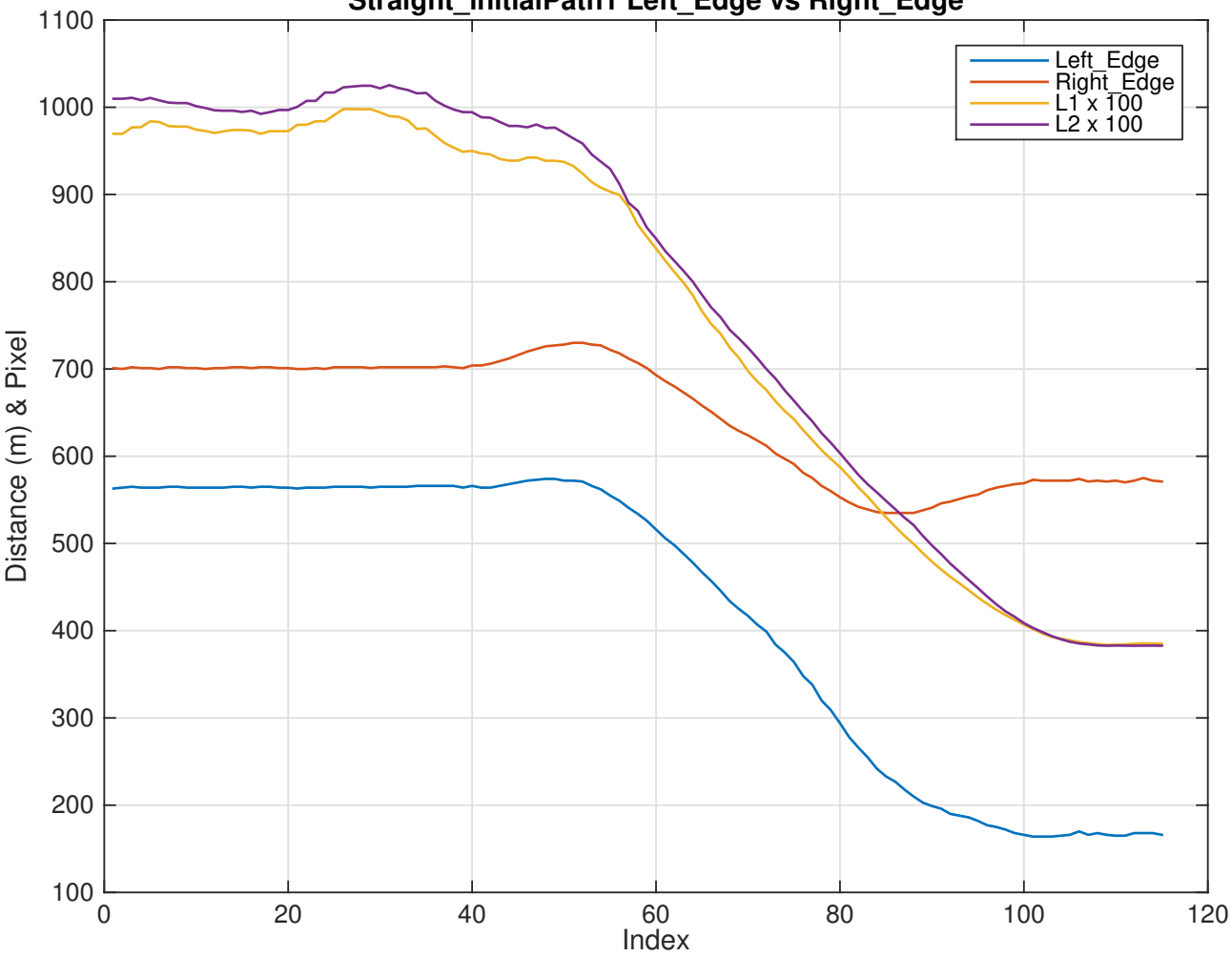
Number_Of_Unique_Paths

King_Pin_Detected

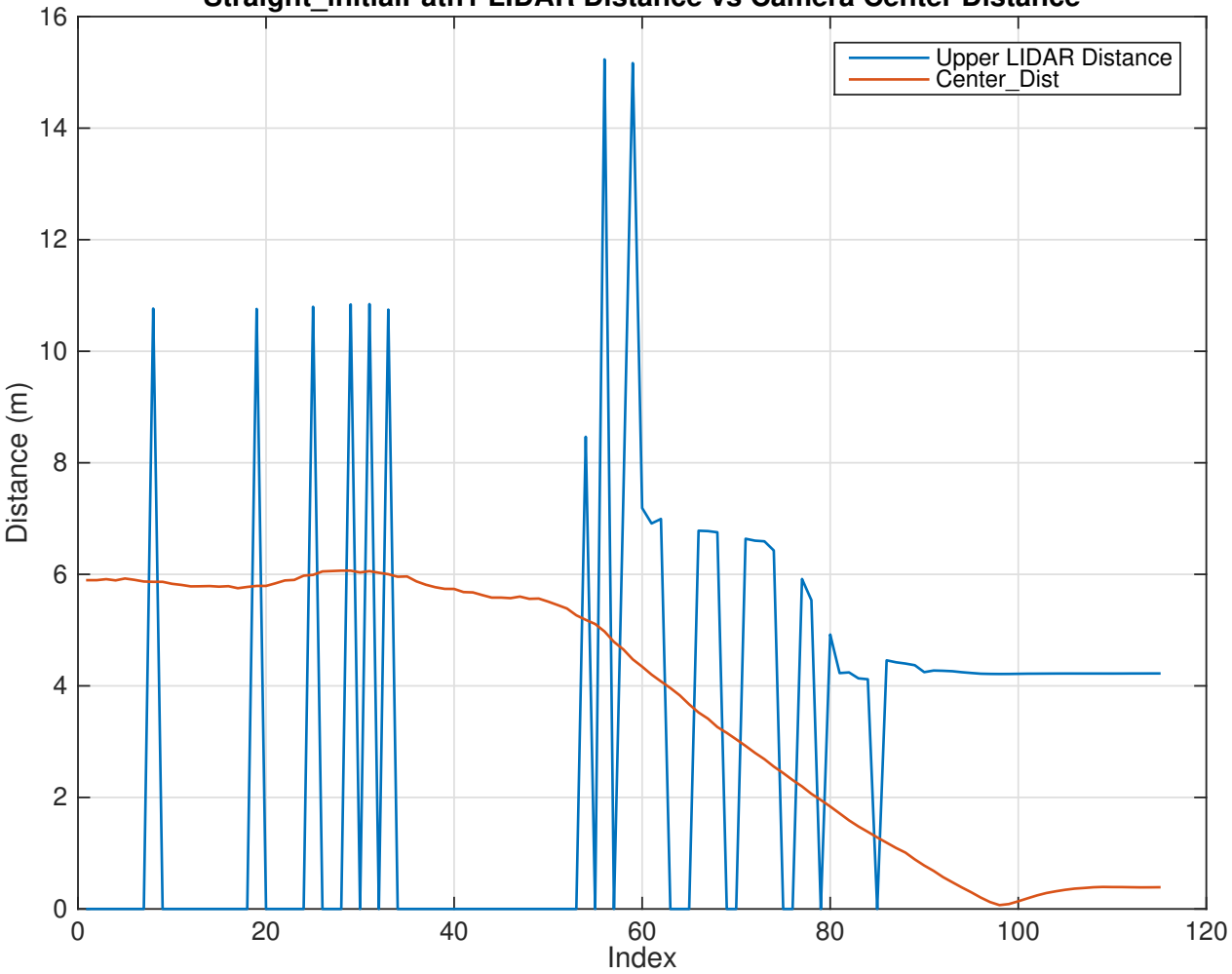
2

false

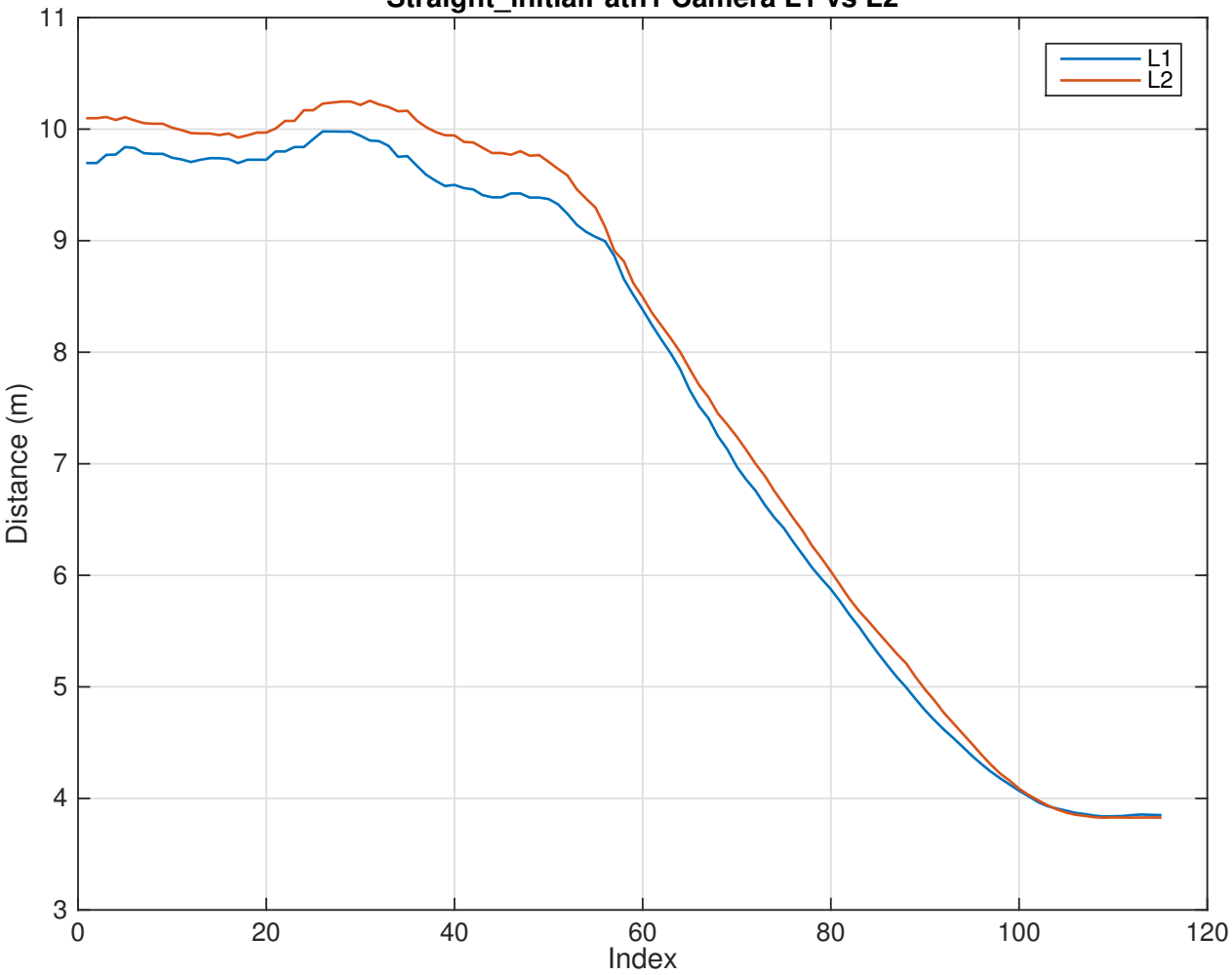
Straight_initialPath1 Left_Edge vs Right_Edge



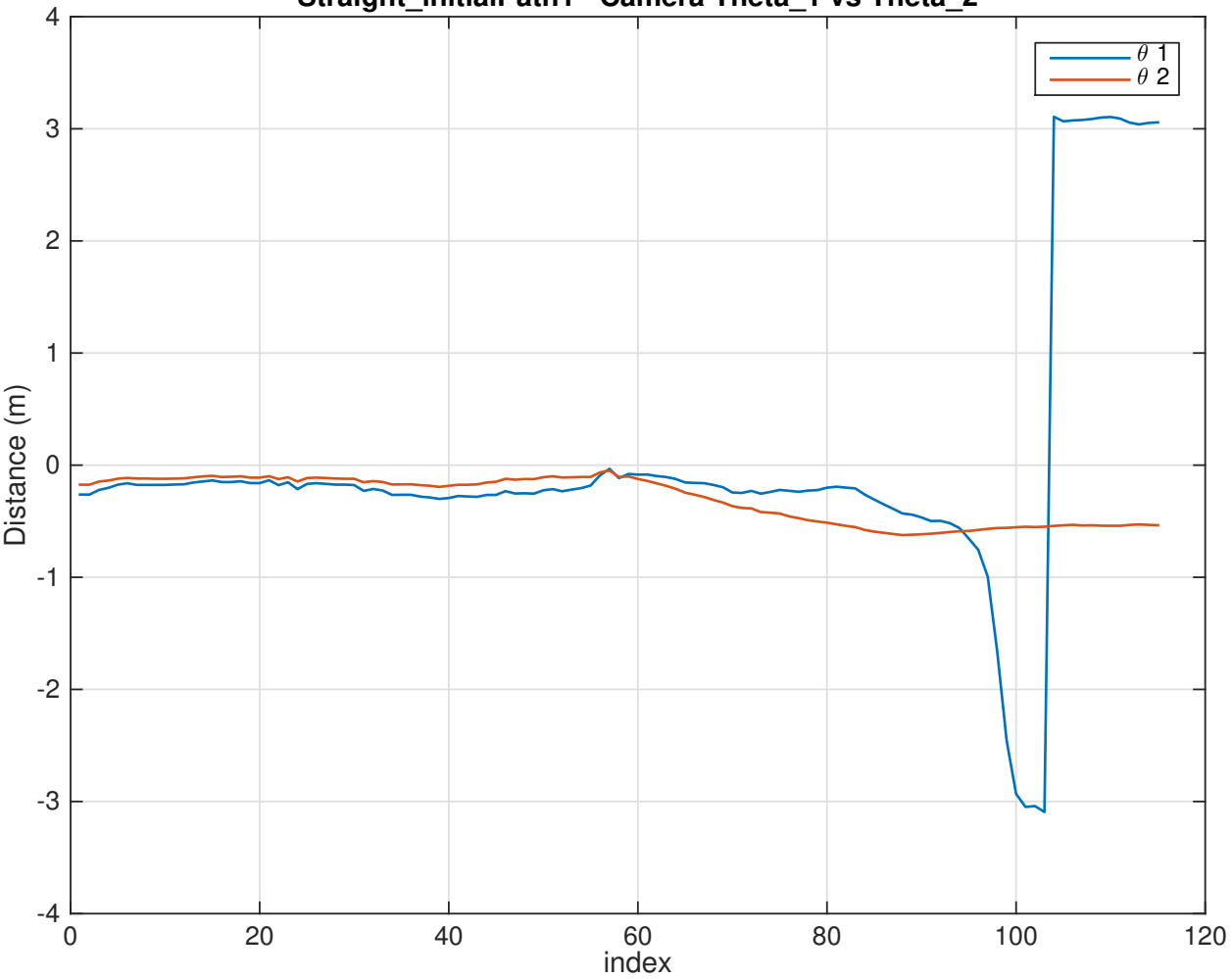
Straight_initialPath1 LIDAR Distance vs Camera Center Distance



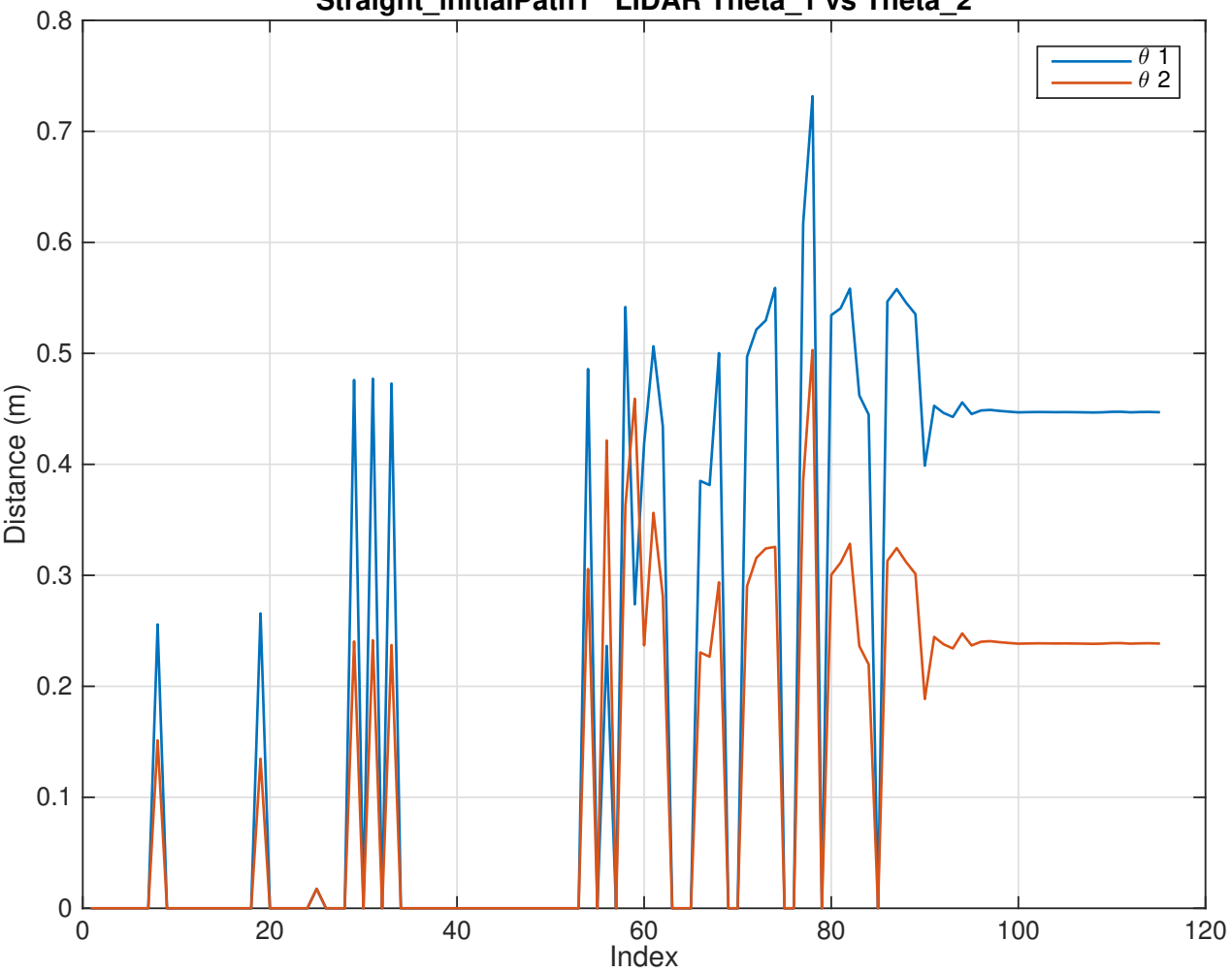
Straight_initialPath1 Camera L1 vs L2



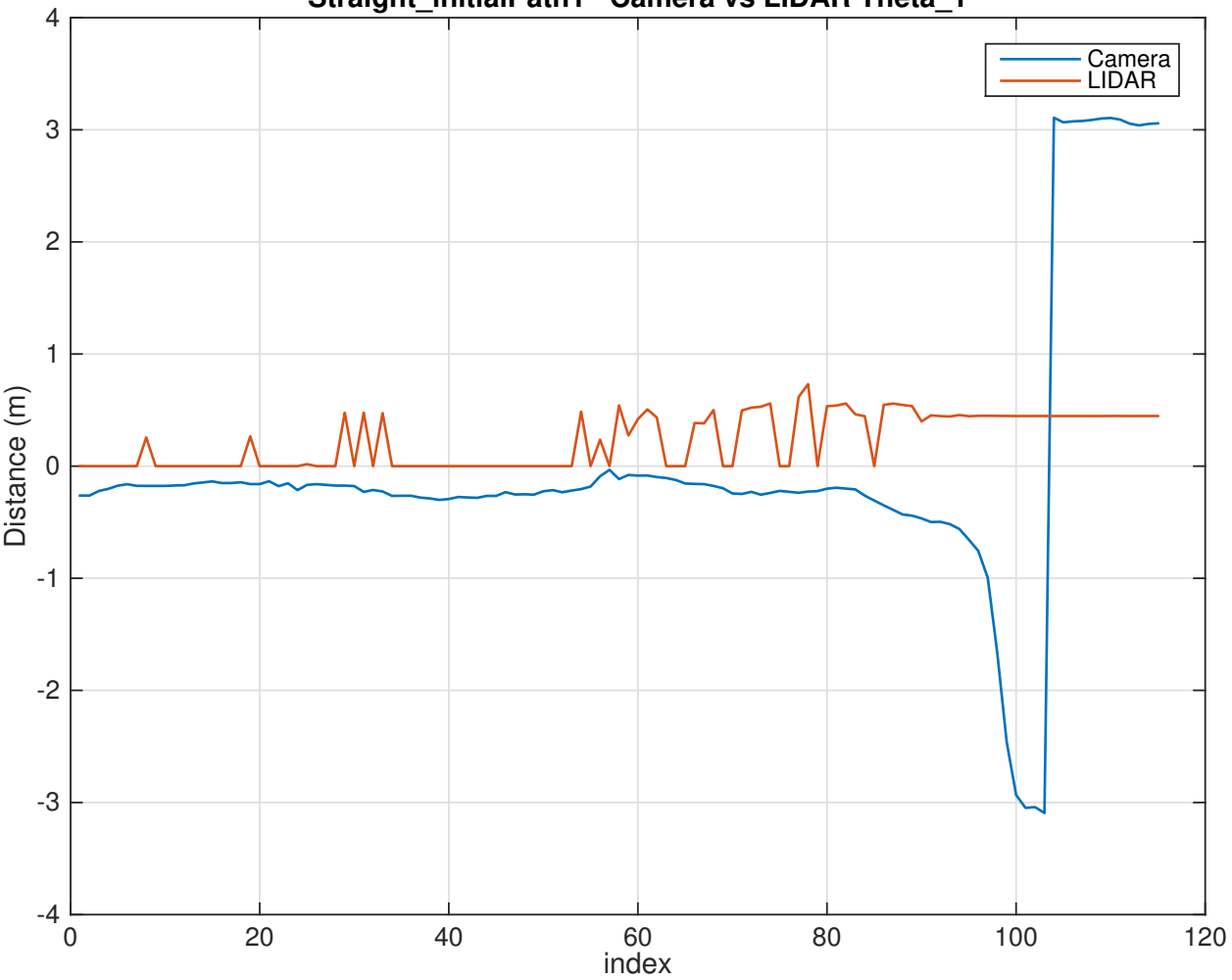
Straight_initialPath1 Camera Theta_1 vs Theta_2



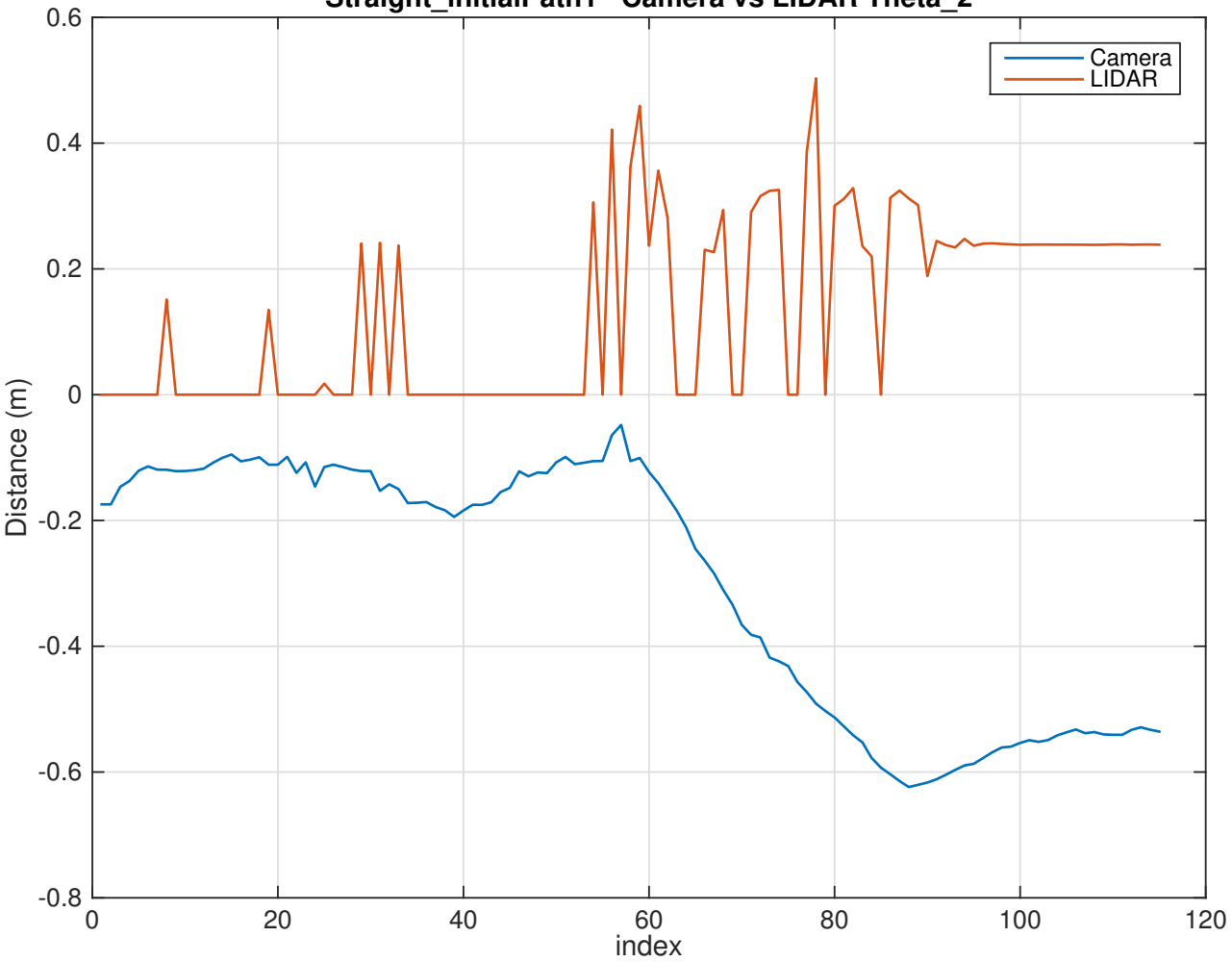
Straight_initialPath1 LIDAR Theta_1 vs Theta_2



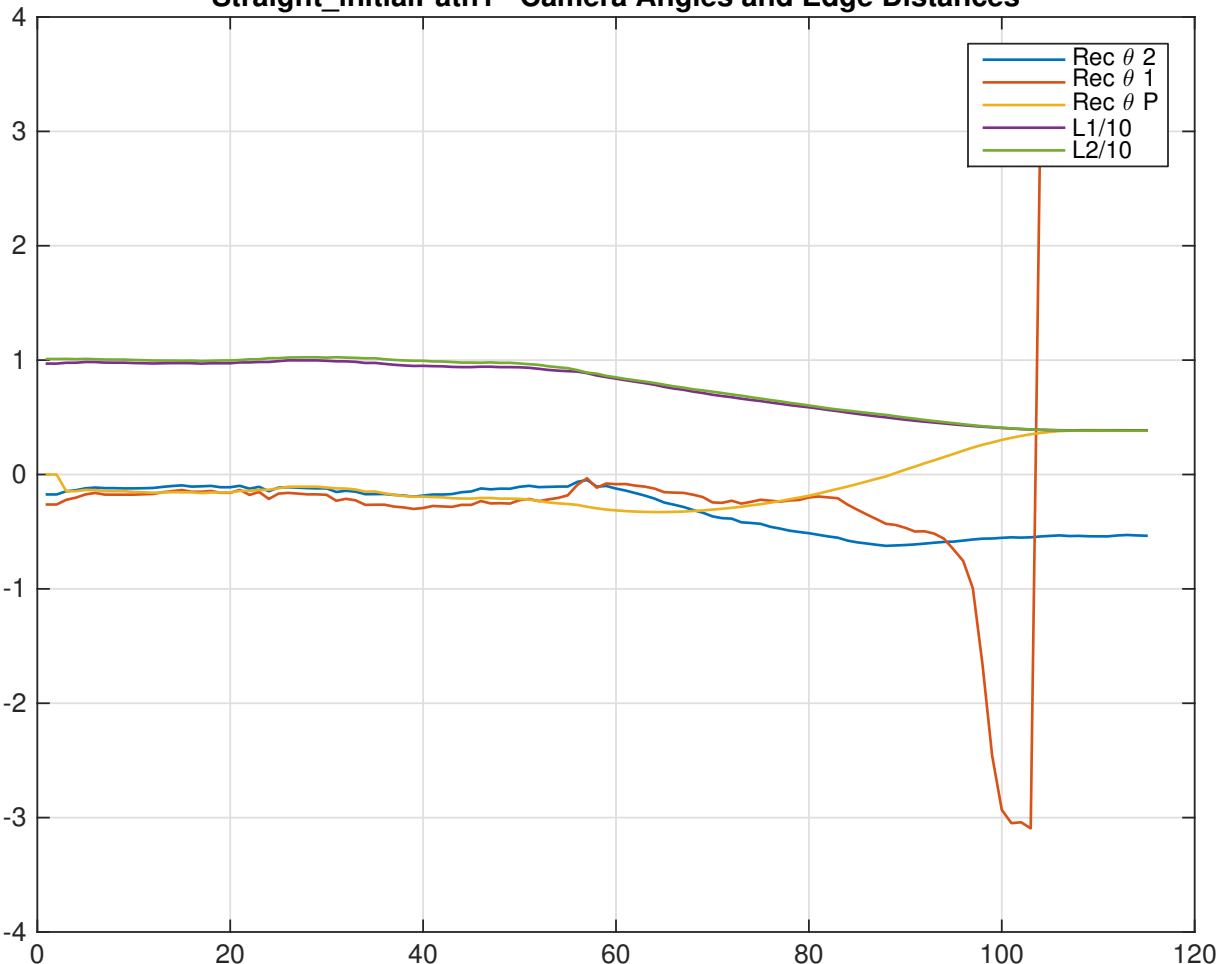
Straight_initialPath1 Camera vs LIDAR Theta_1



Straight_initialPath1 Camera vs LIDAR Theta_2



Straight_initialPath1 Camera Angles and Edge Distances



Straight_initialPath1 Calculated vs. Actual Steering

