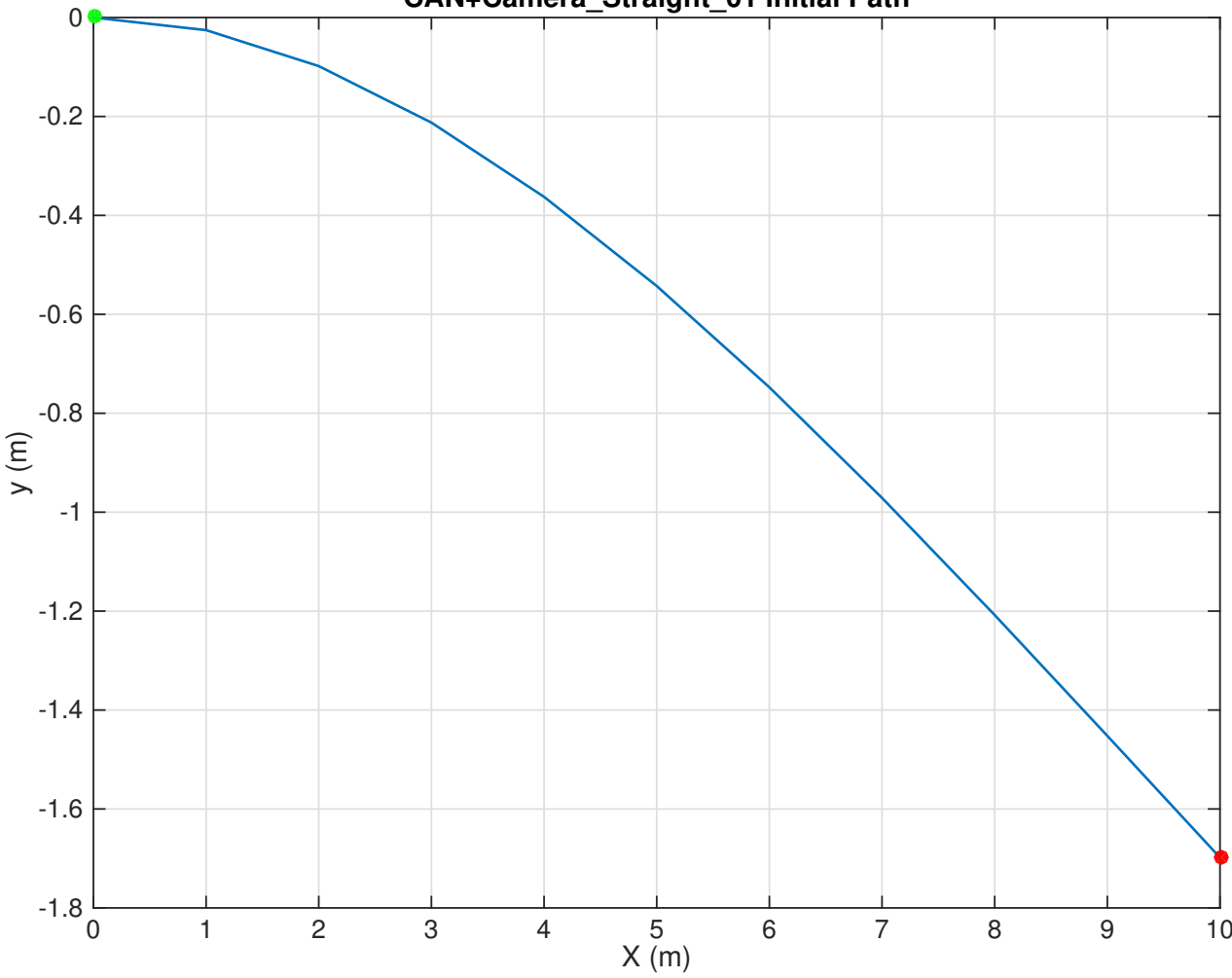
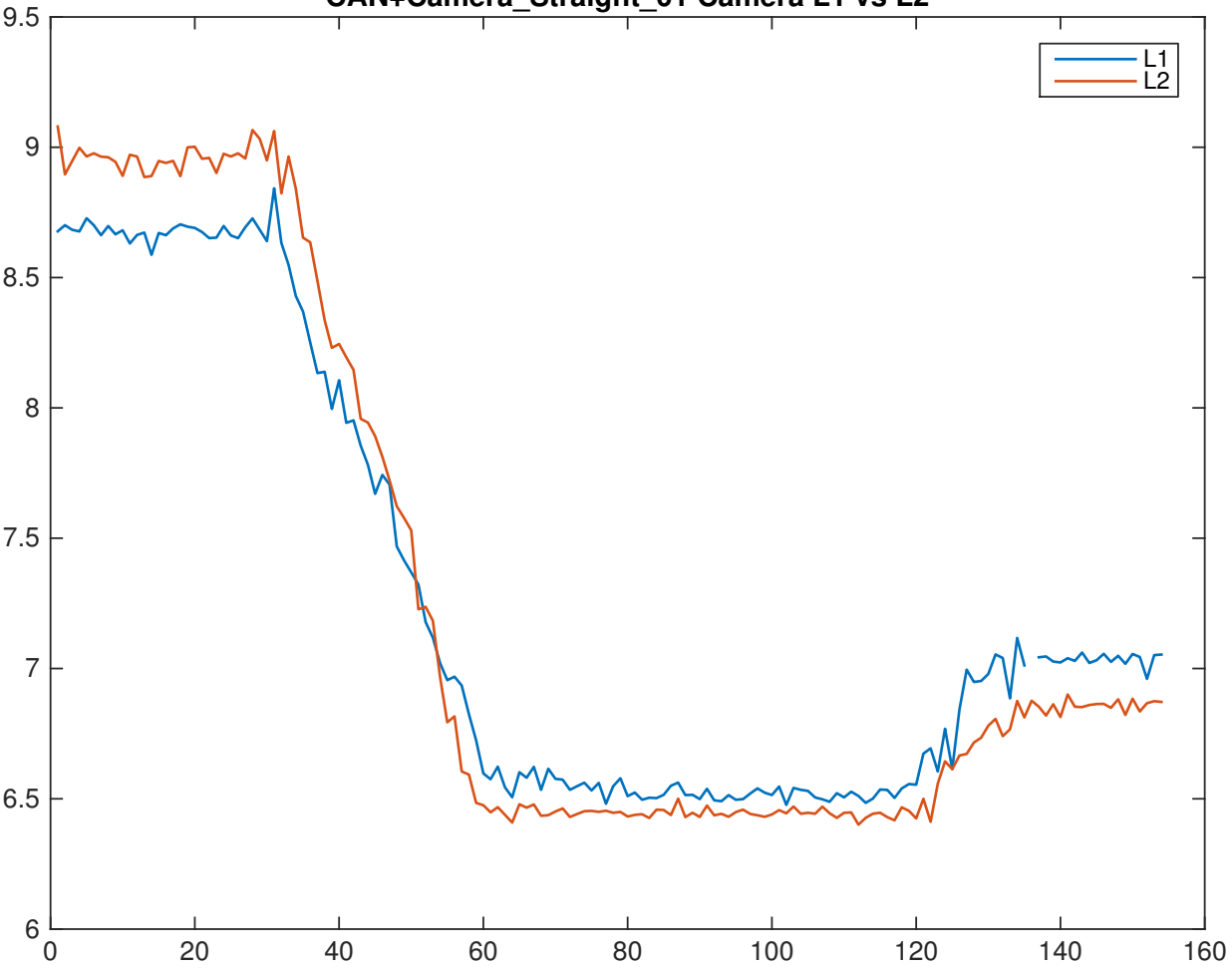


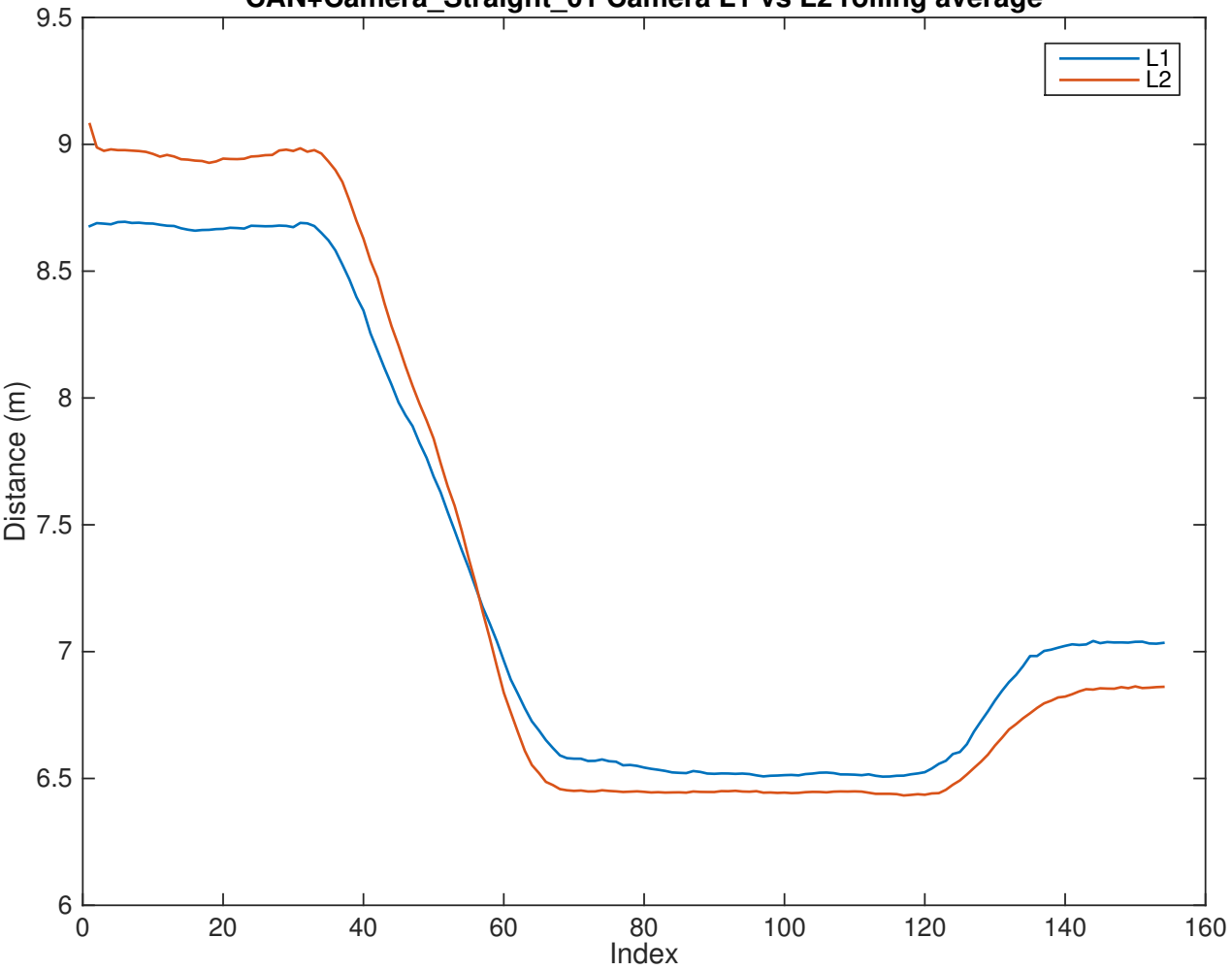
CAN+Camera_Straight_01 Initial Path



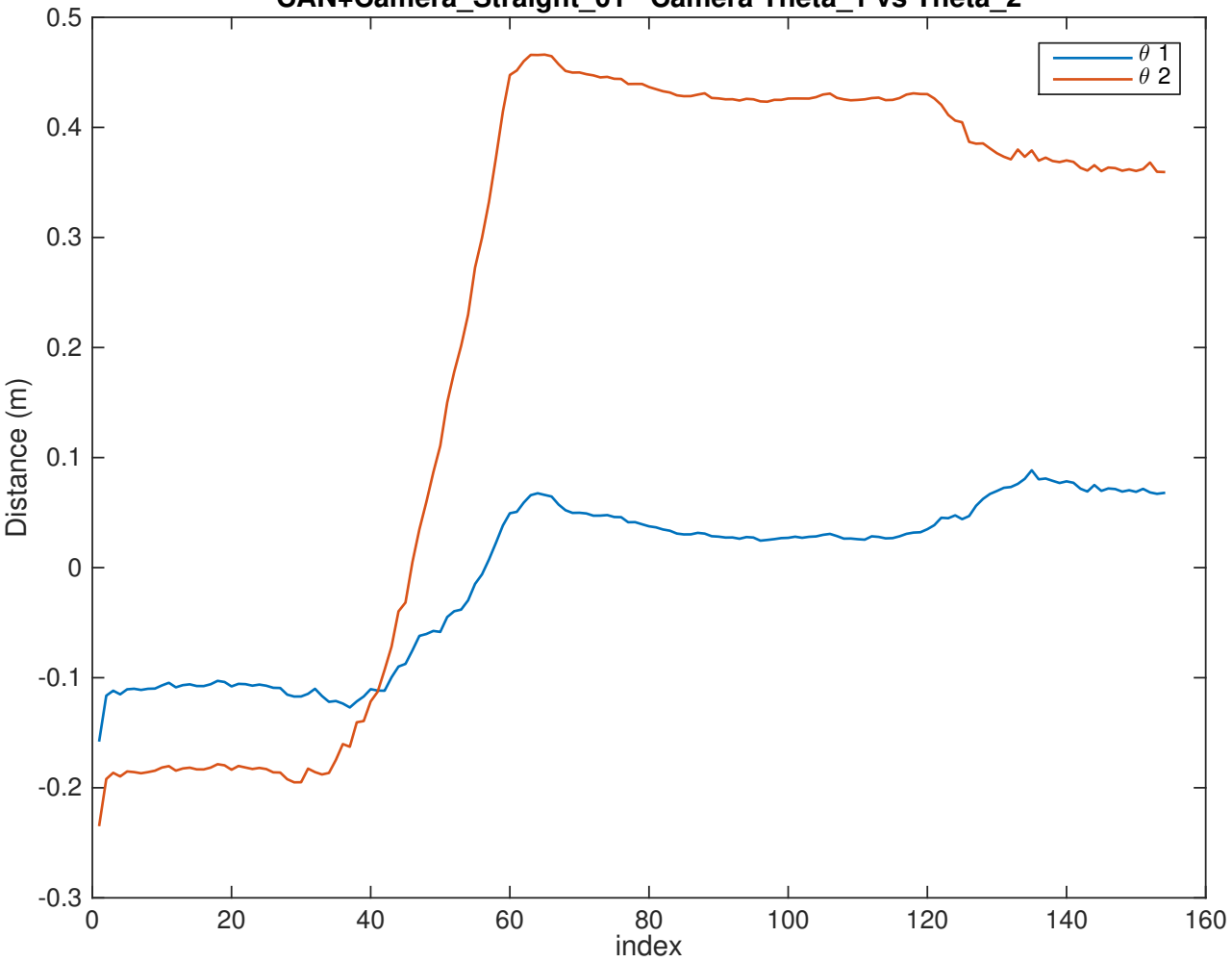
CAN+Camera_Straight_01 Camera L1 vs L2



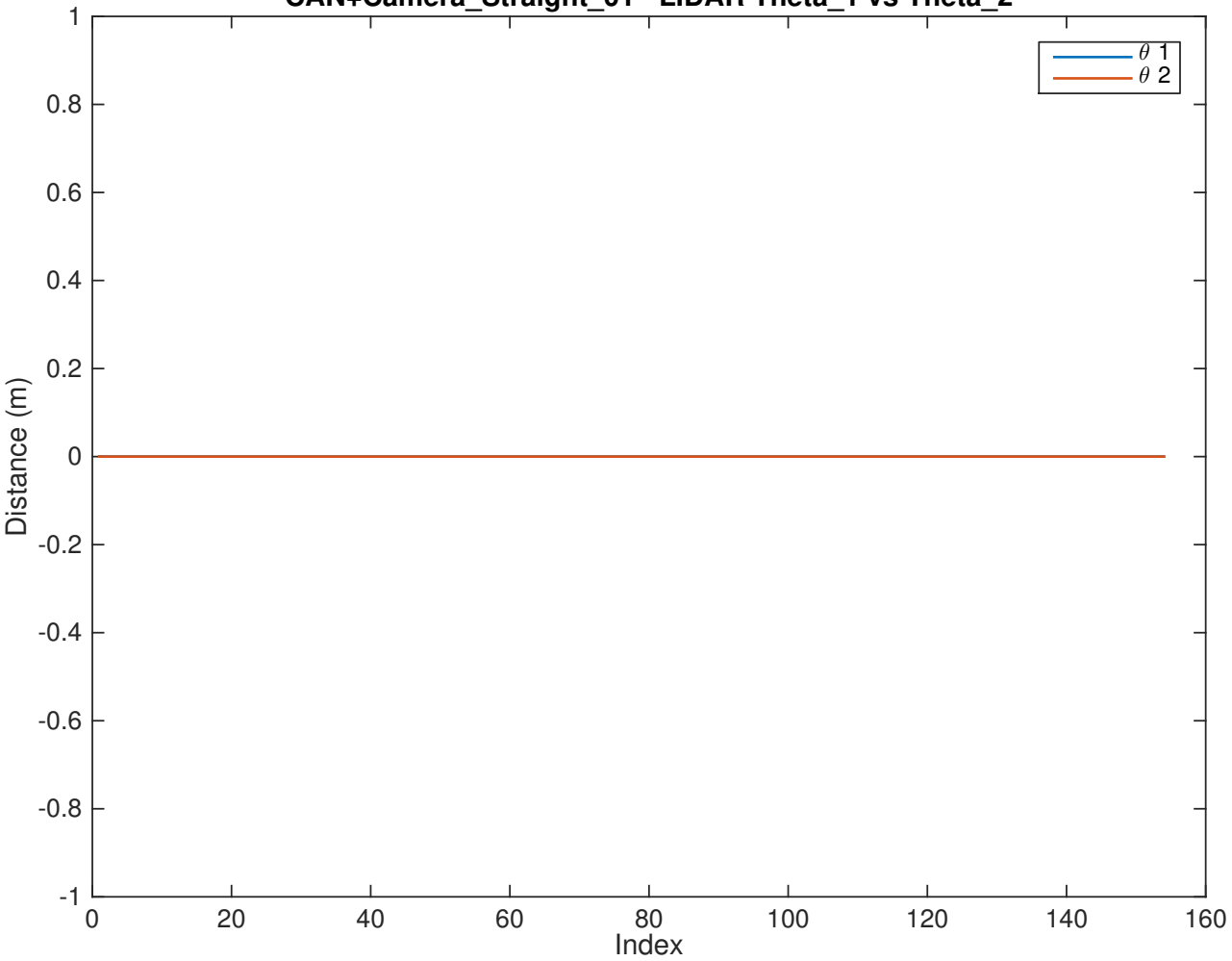
CAN+Camera_Straight_01 Camera L1 vs L2 rolling average



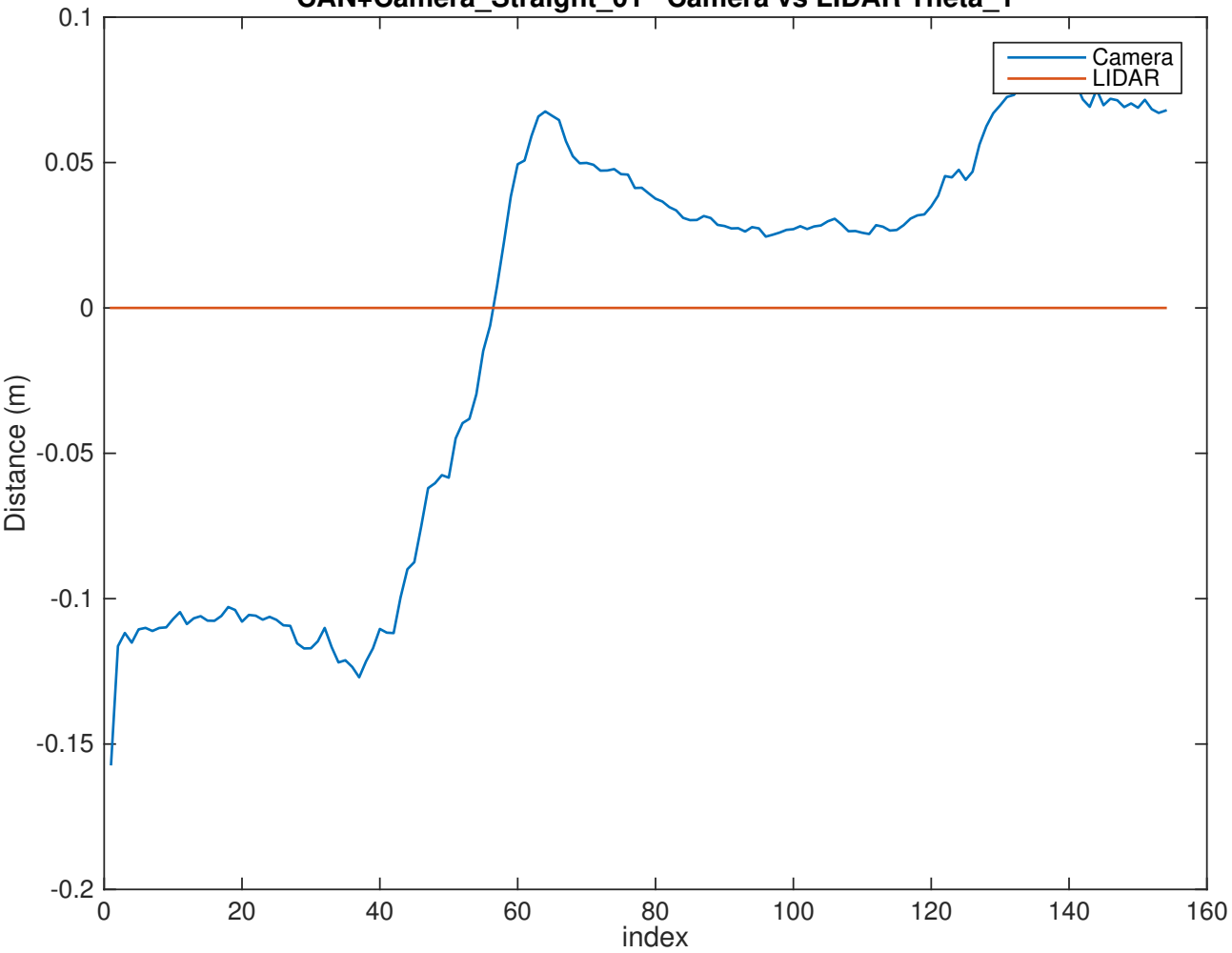
CAN+Camera_Straight_01 Camera Theta_1 vs Theta_2



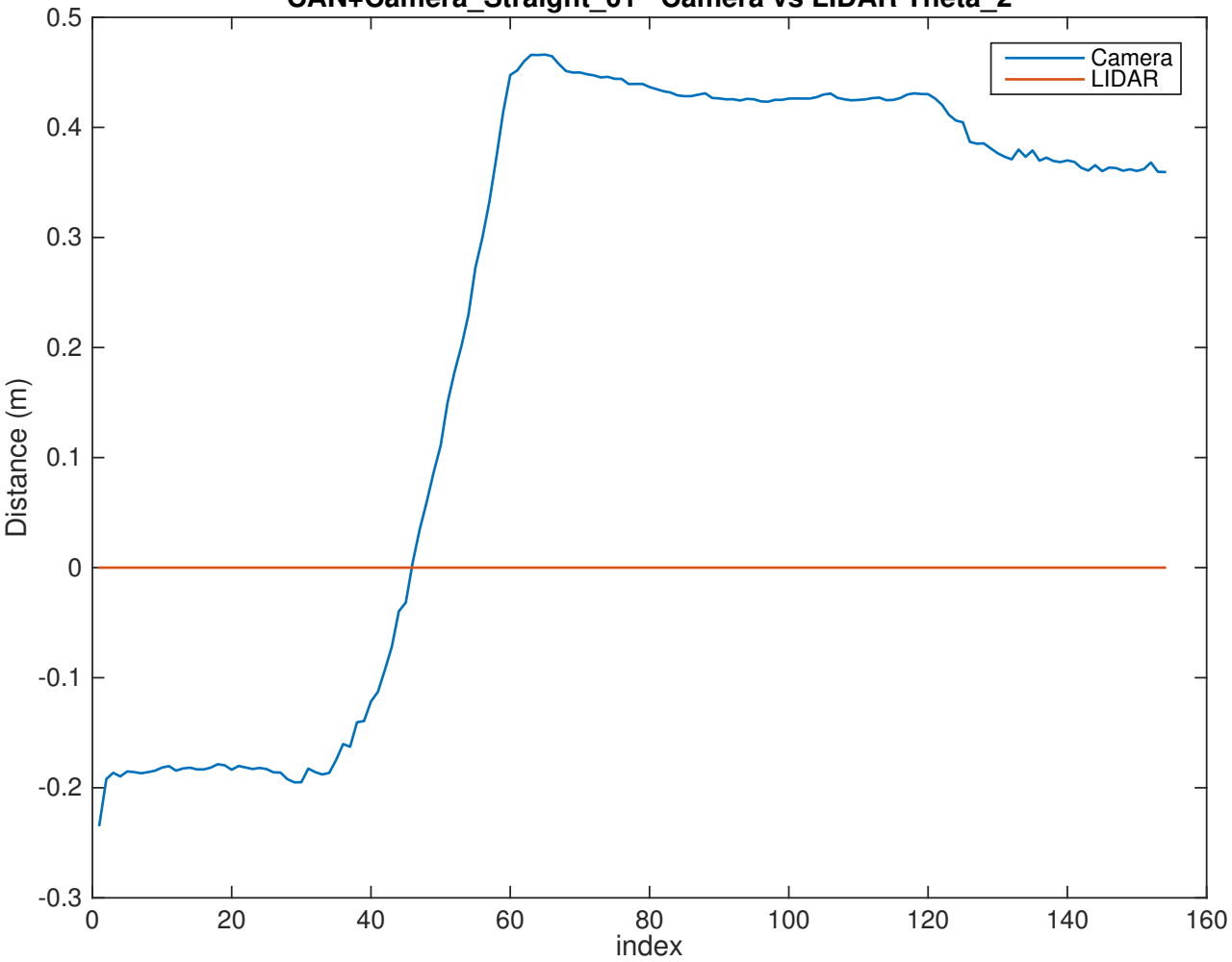
CAN+Camera_Straight_01 LIDAR Theta_1 vs Theta_2



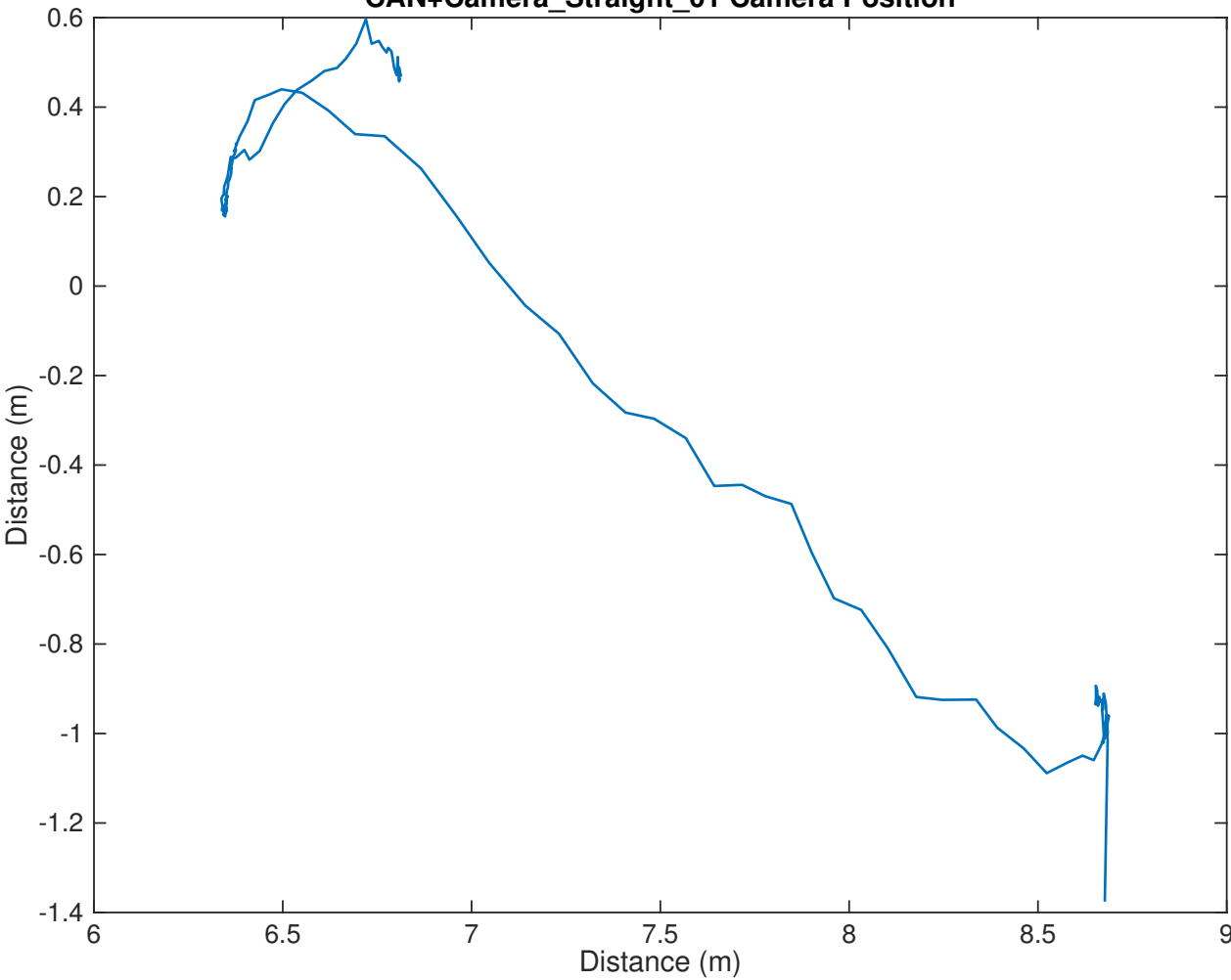
CAN+Camera_Straight_01 Camera vs LIDAR Theta_1



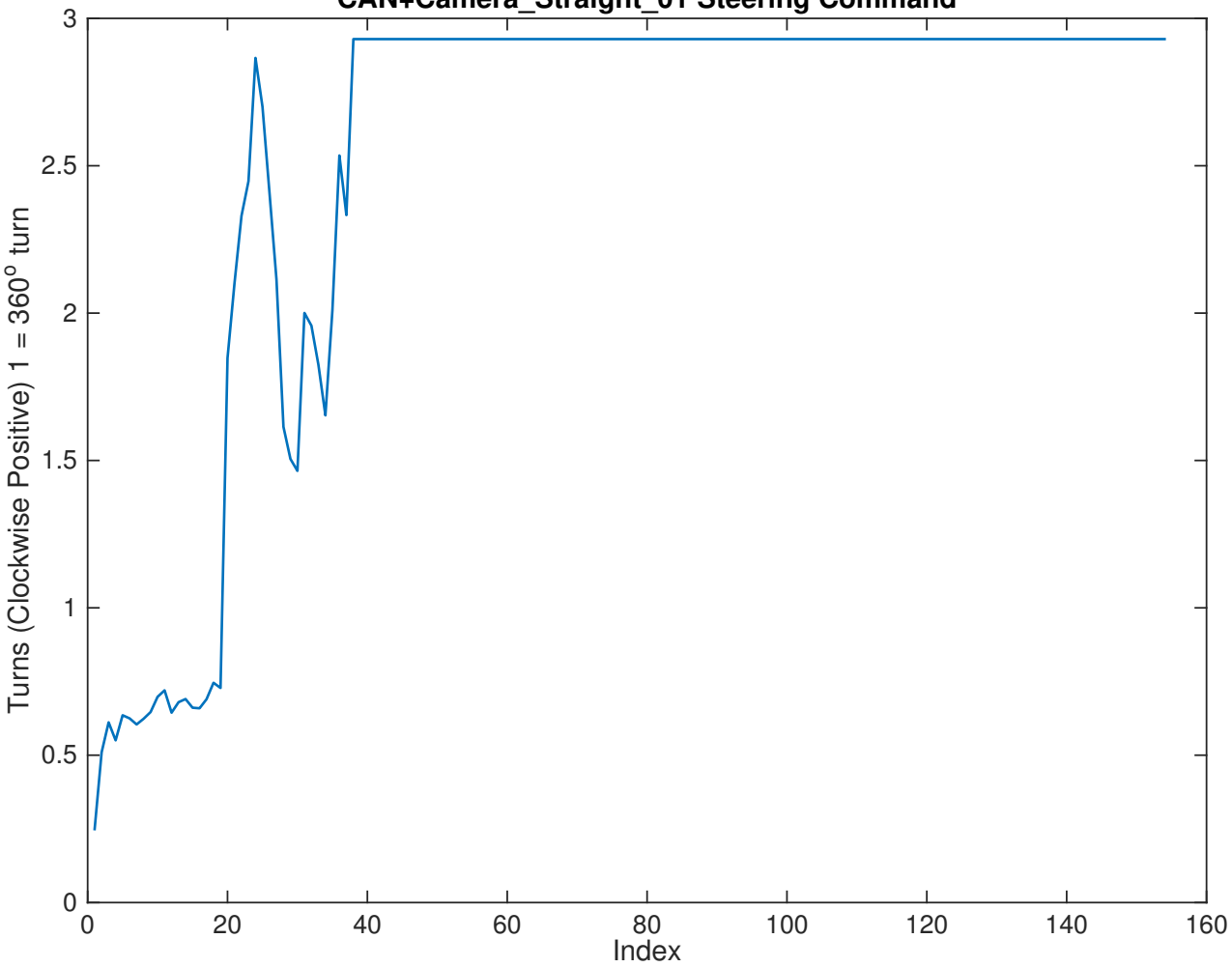
CAN+Camera_Straight_01 Camera vs LIDAR Theta_2



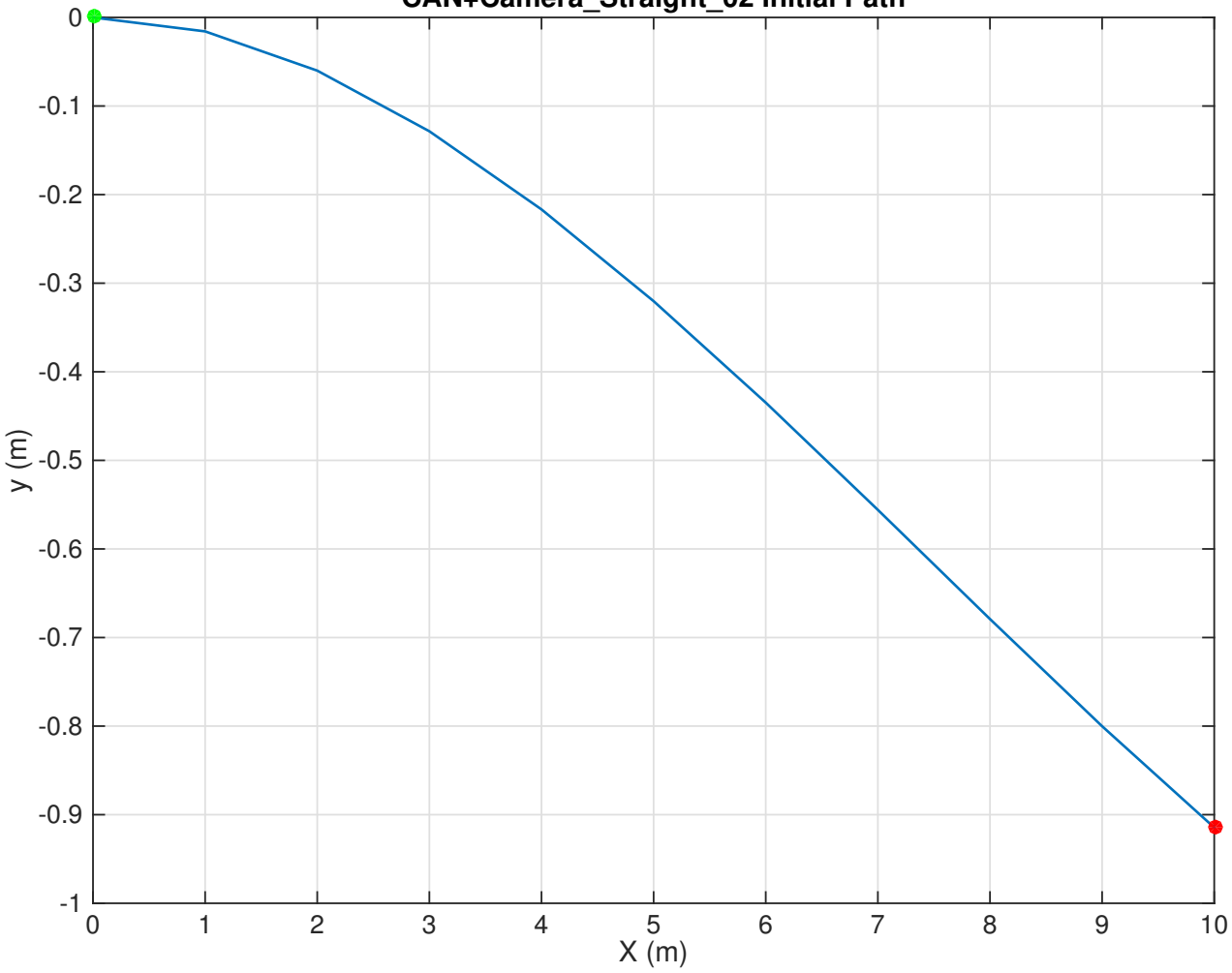
CAN+Camera_Straight_01 Camera Position



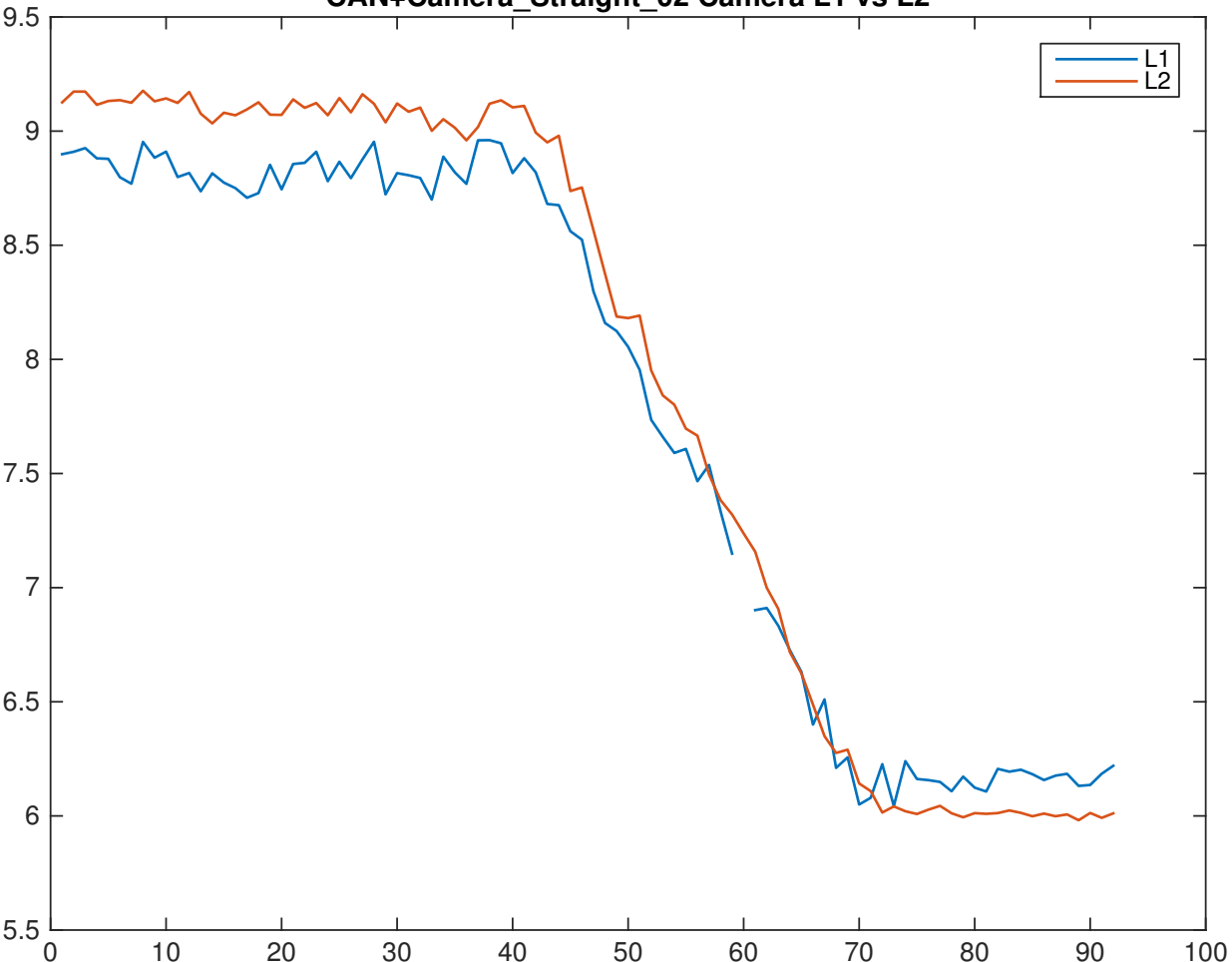
CAN+Camera_Straight_01 Steering Command



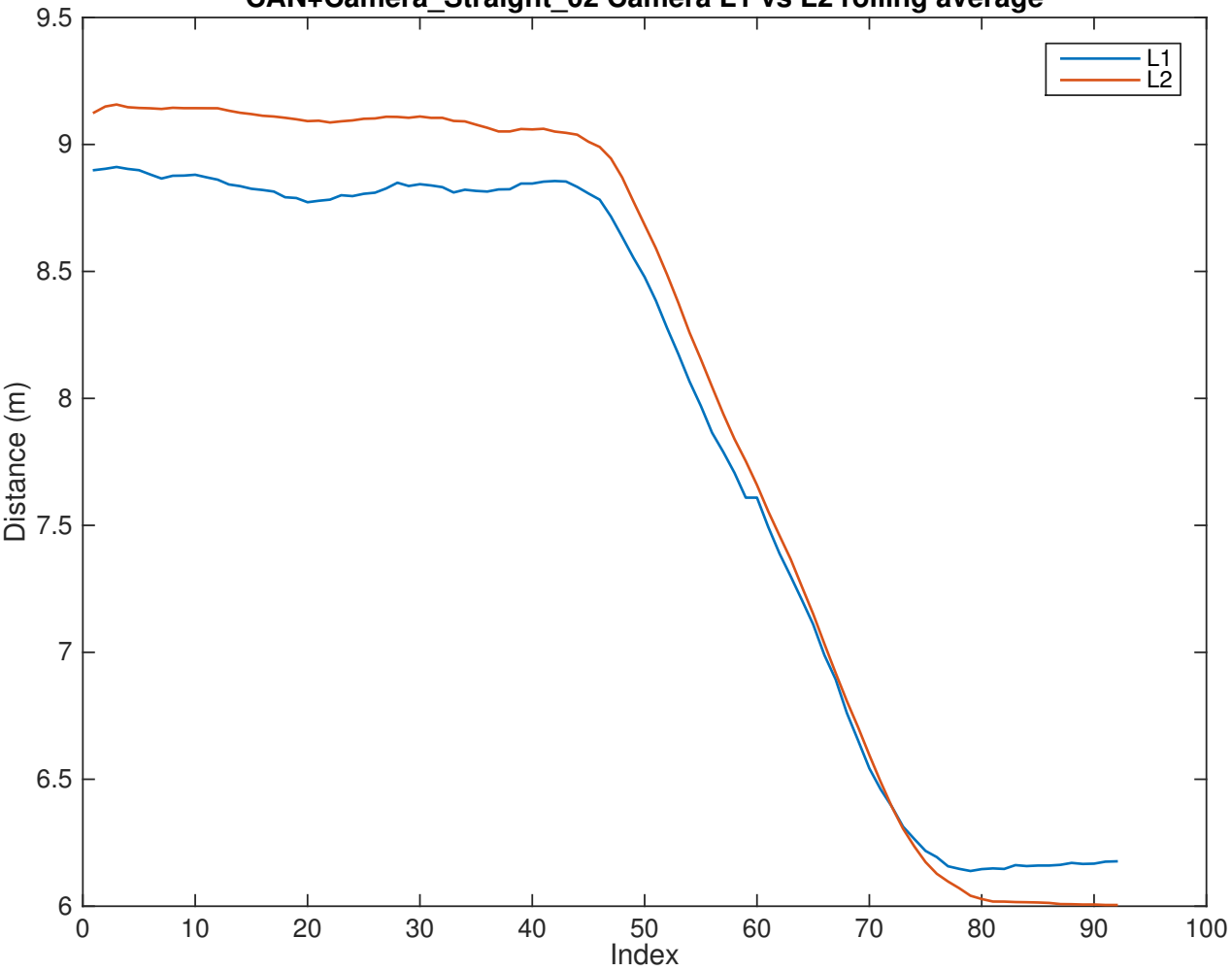
CAN+Camera_Straight_02 Initial Path



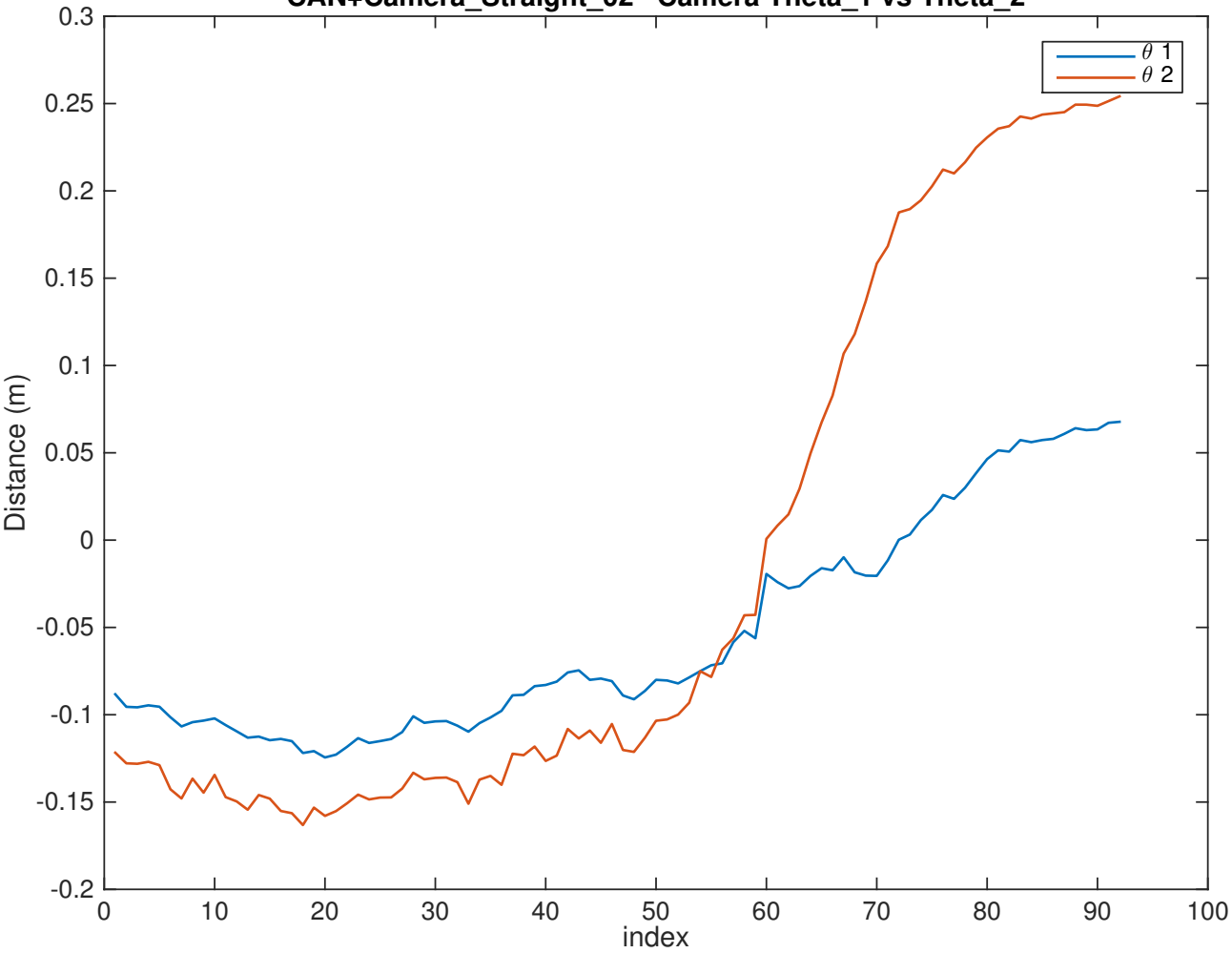
CAN+Camera_Straight_02 Camera L1 vs L2



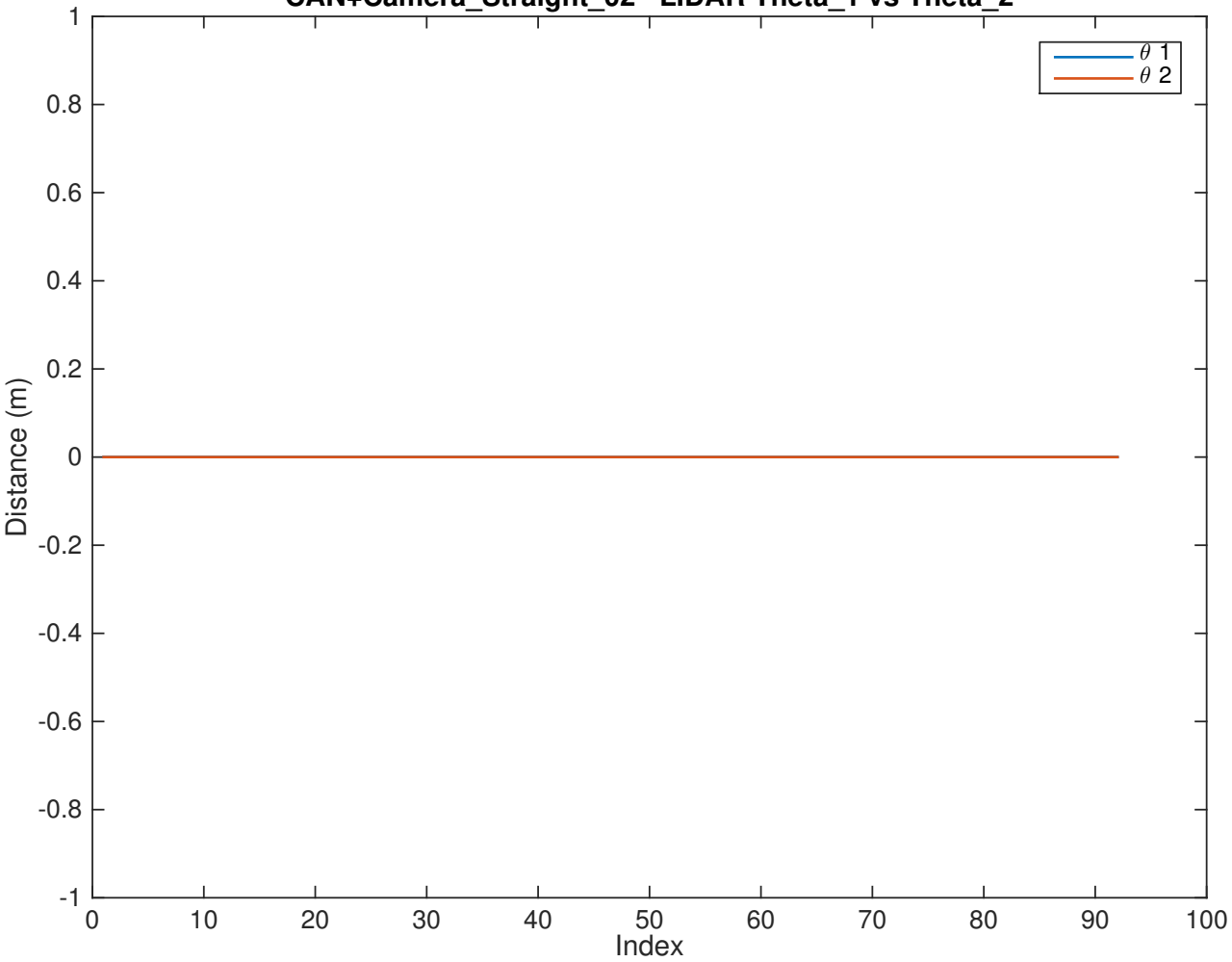
CAN+Camera_Straight_02 Camera L1 vs L2 rolling average



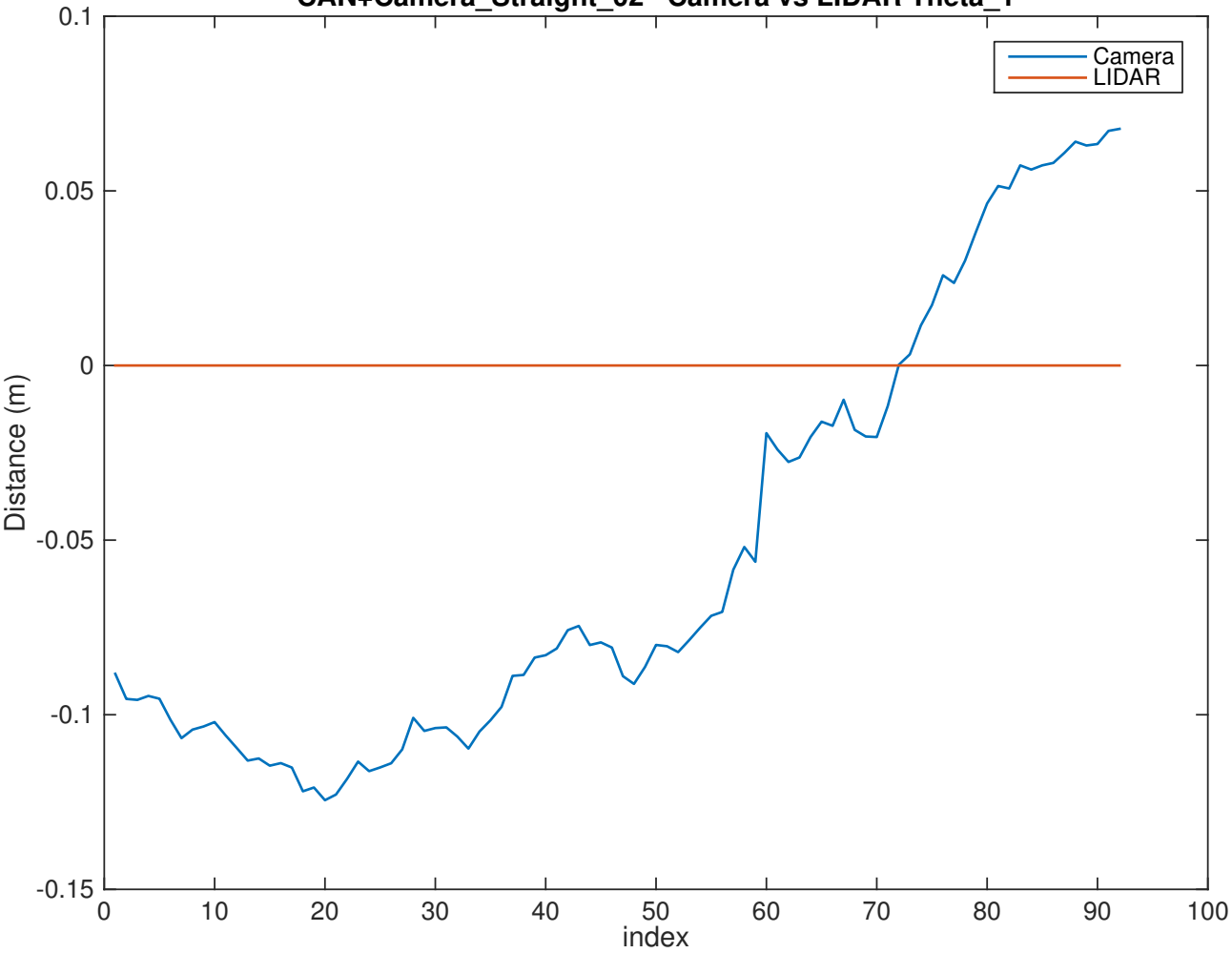
CAN+Camera_Straight_02 Camera Theta_1 vs Theta_2



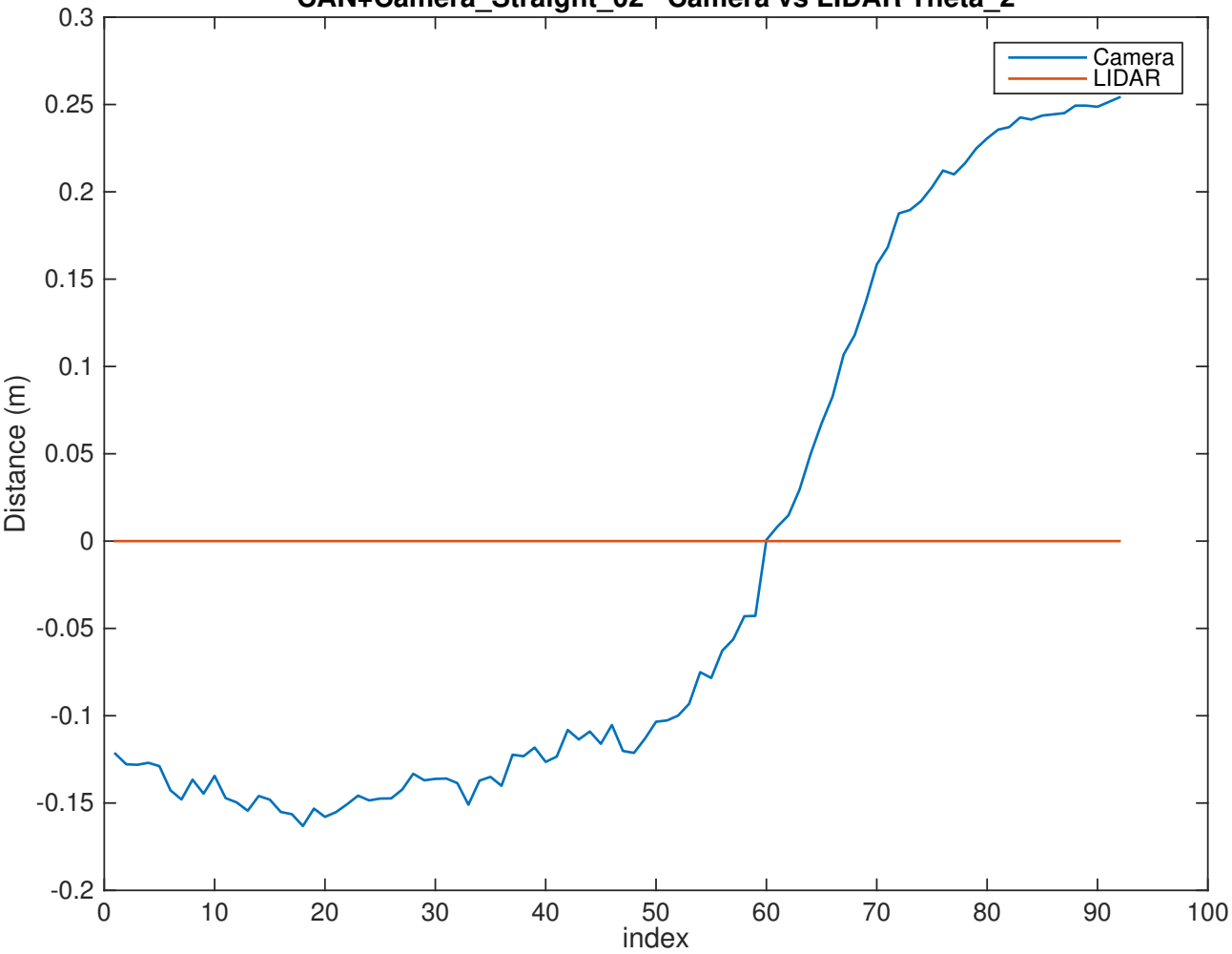
CAN+Camera_Straight_02 LIDAR Theta_1 vs Theta_2



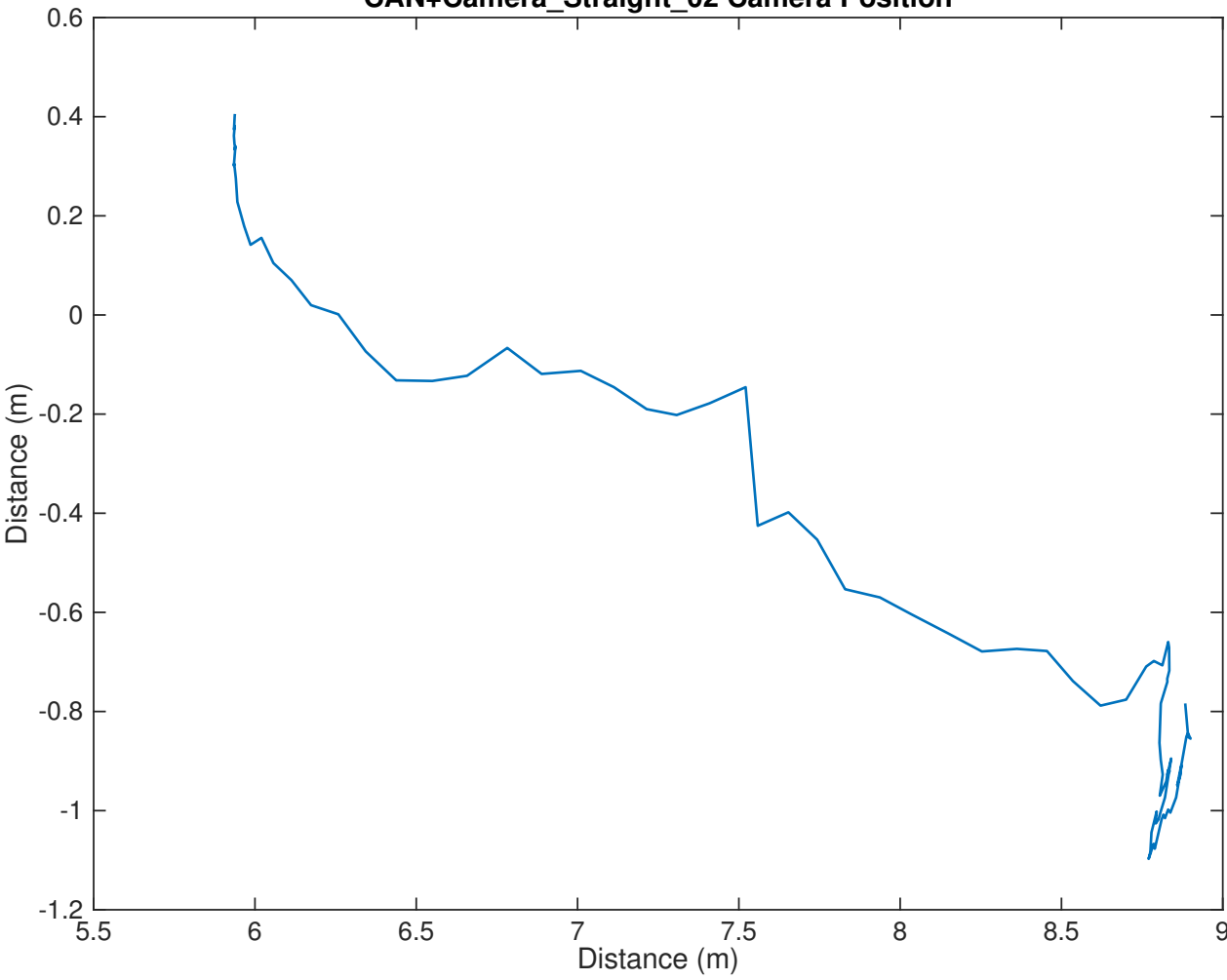
CAN+Camera_Straight_02 Camera vs LIDAR Theta_1



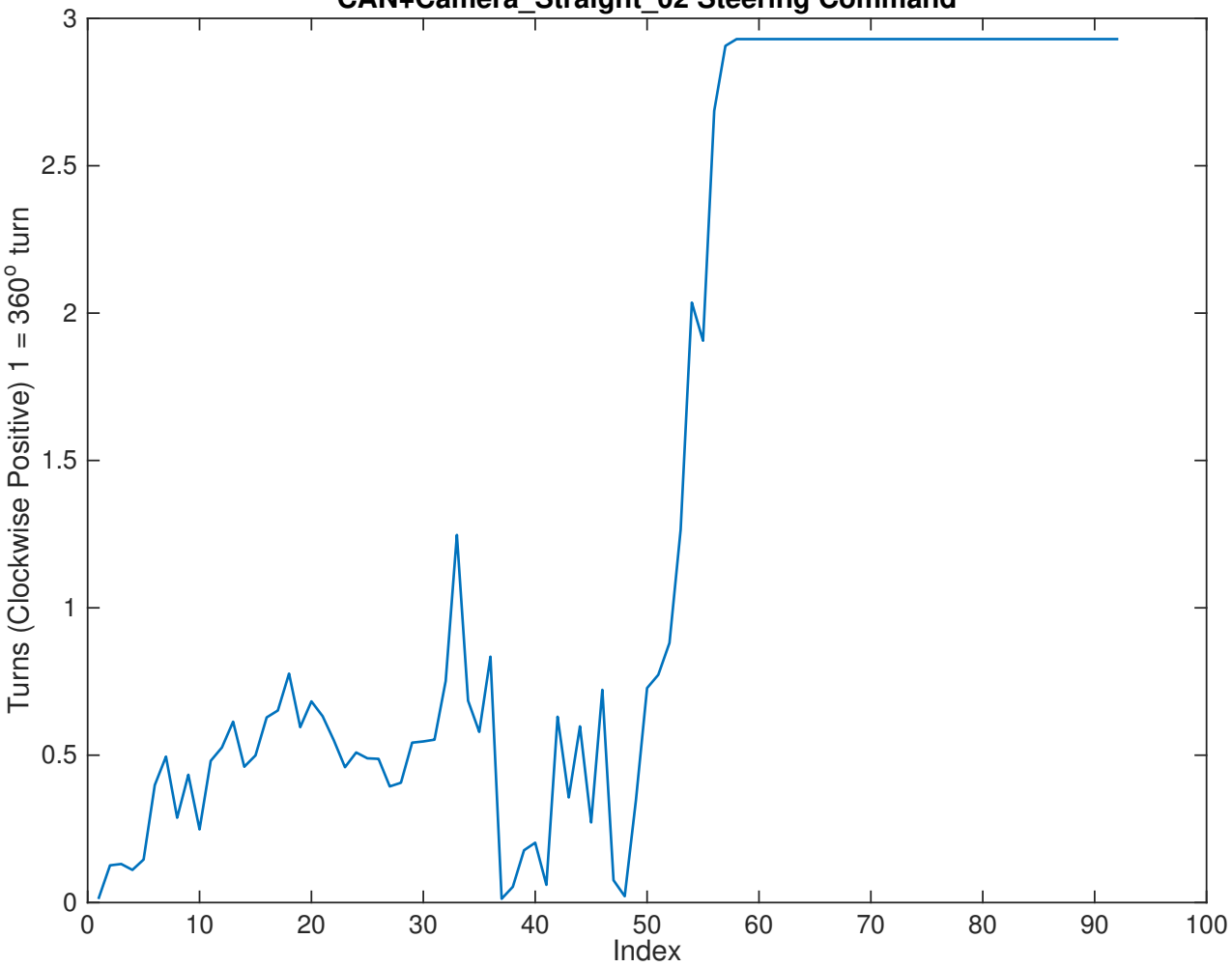
CAN+Camera_Straight_02 Camera vs LIDAR Theta_2



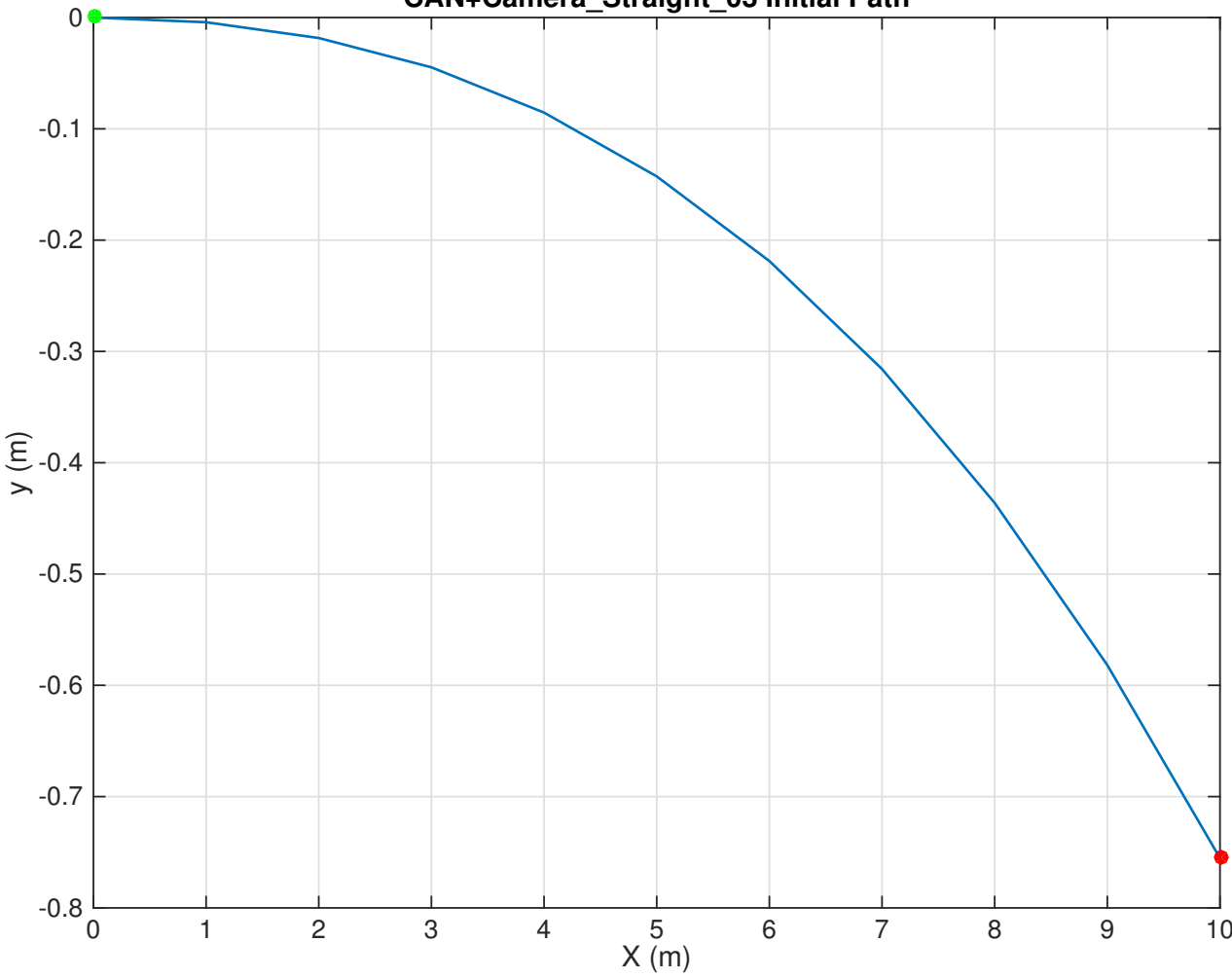
CAN+Camera_Straight_02 Camera Position



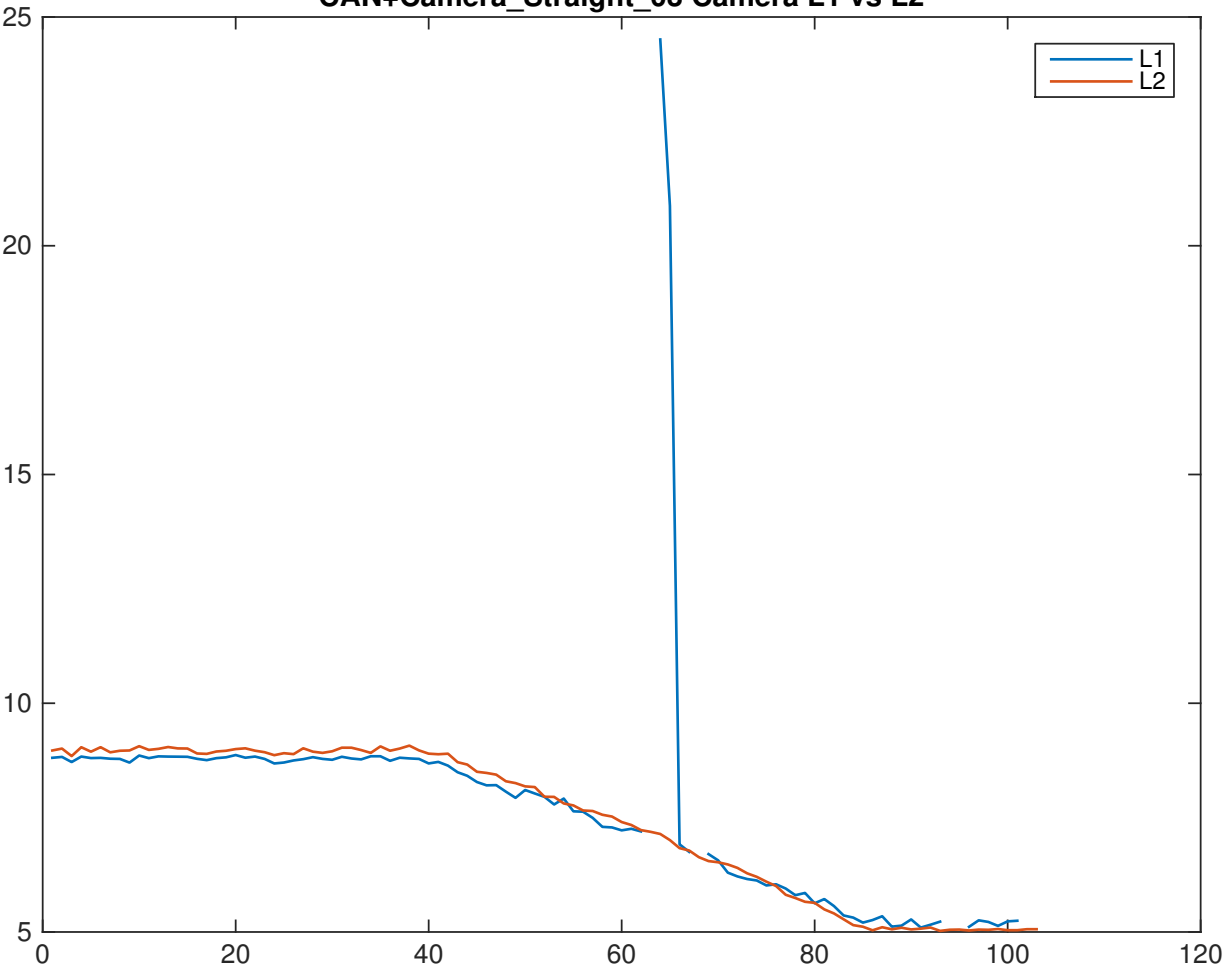
CAN+Camera_Straight_02 Steering Command



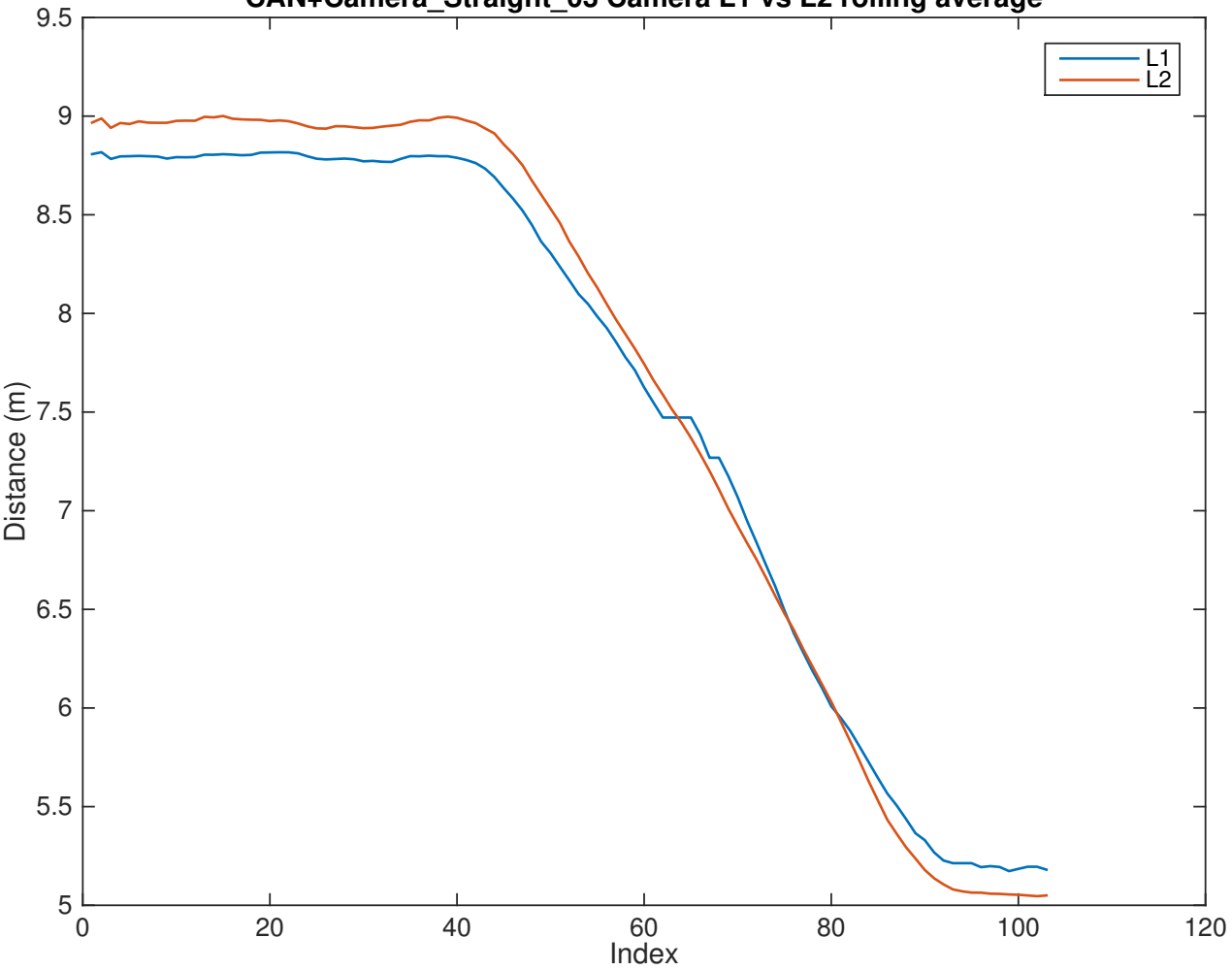
CAN+Camera_Straight_03 Initial Path



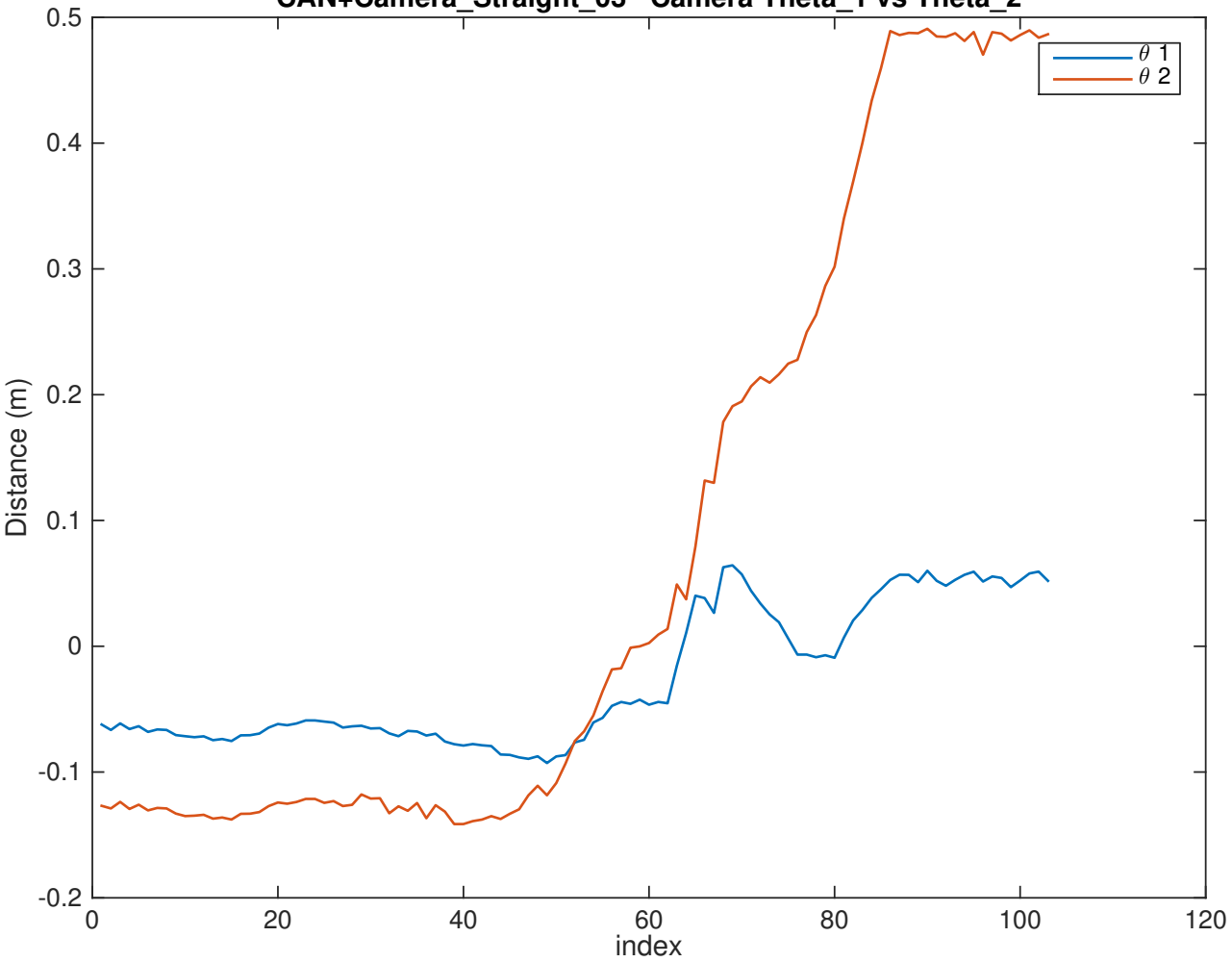
CAN+Camera_Straight_03 Camera L1 vs L2



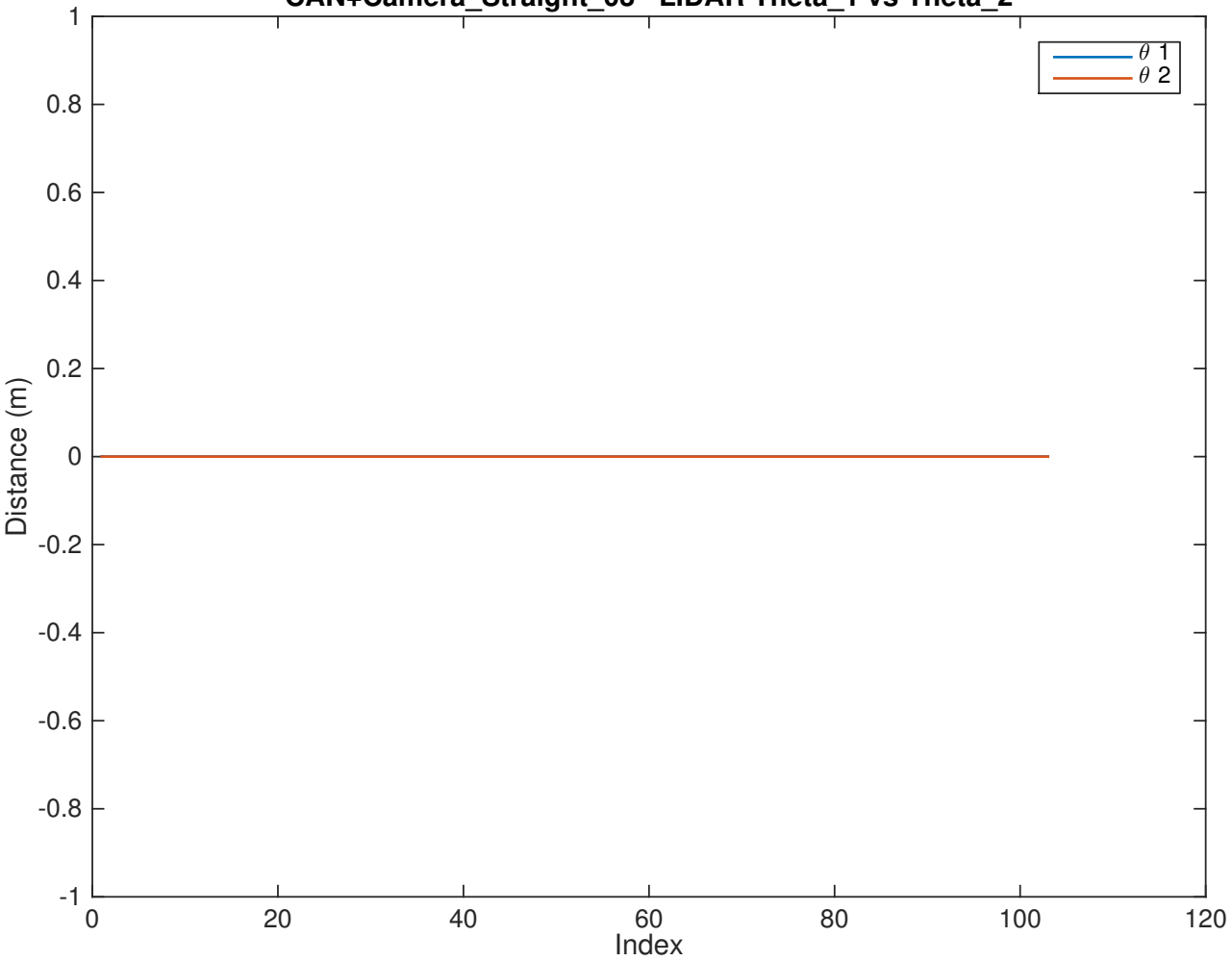
CAN+Camera_Straight_03 Camera L1 vs L2 rolling average



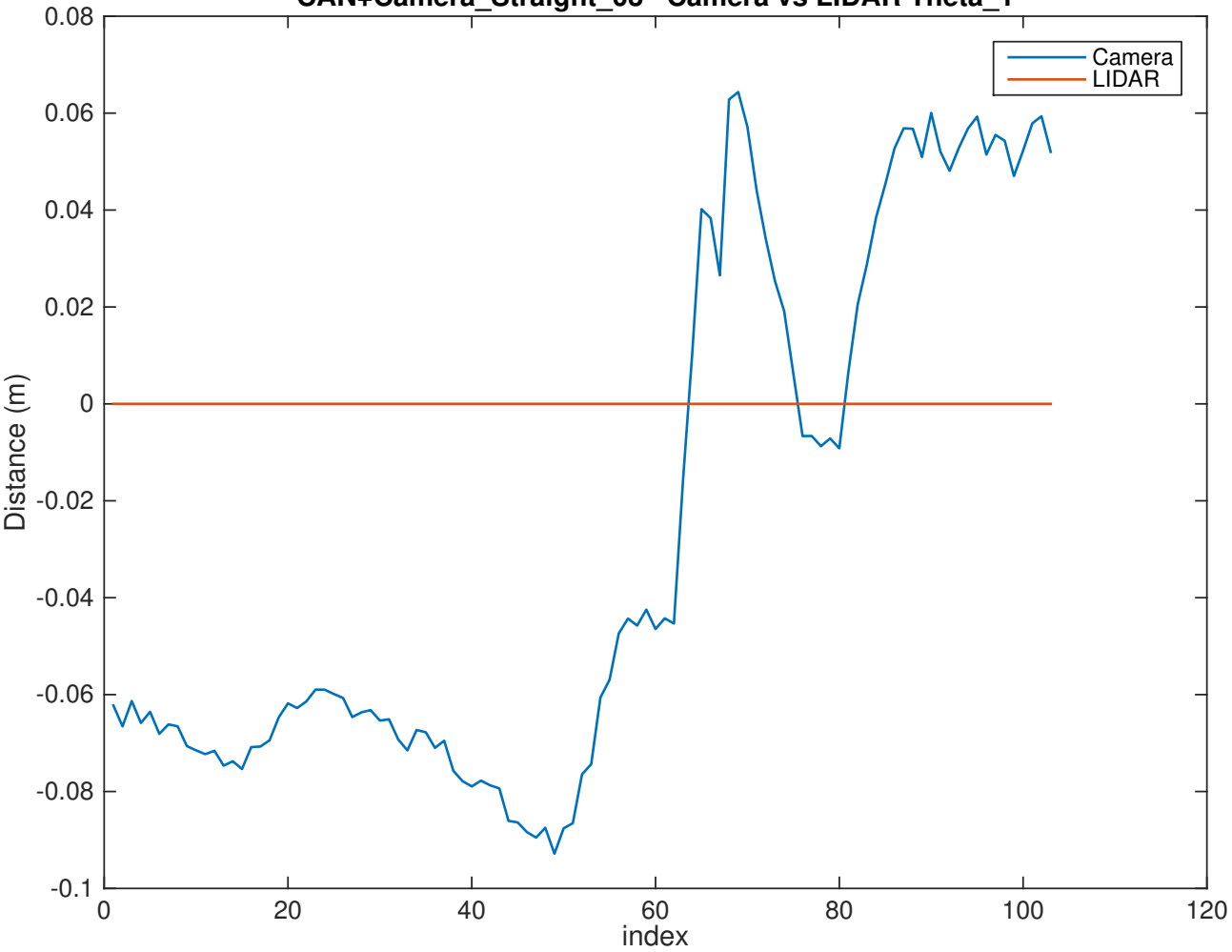
CAN+Camera_Straight_03 Camera Theta_1 vs Theta_2



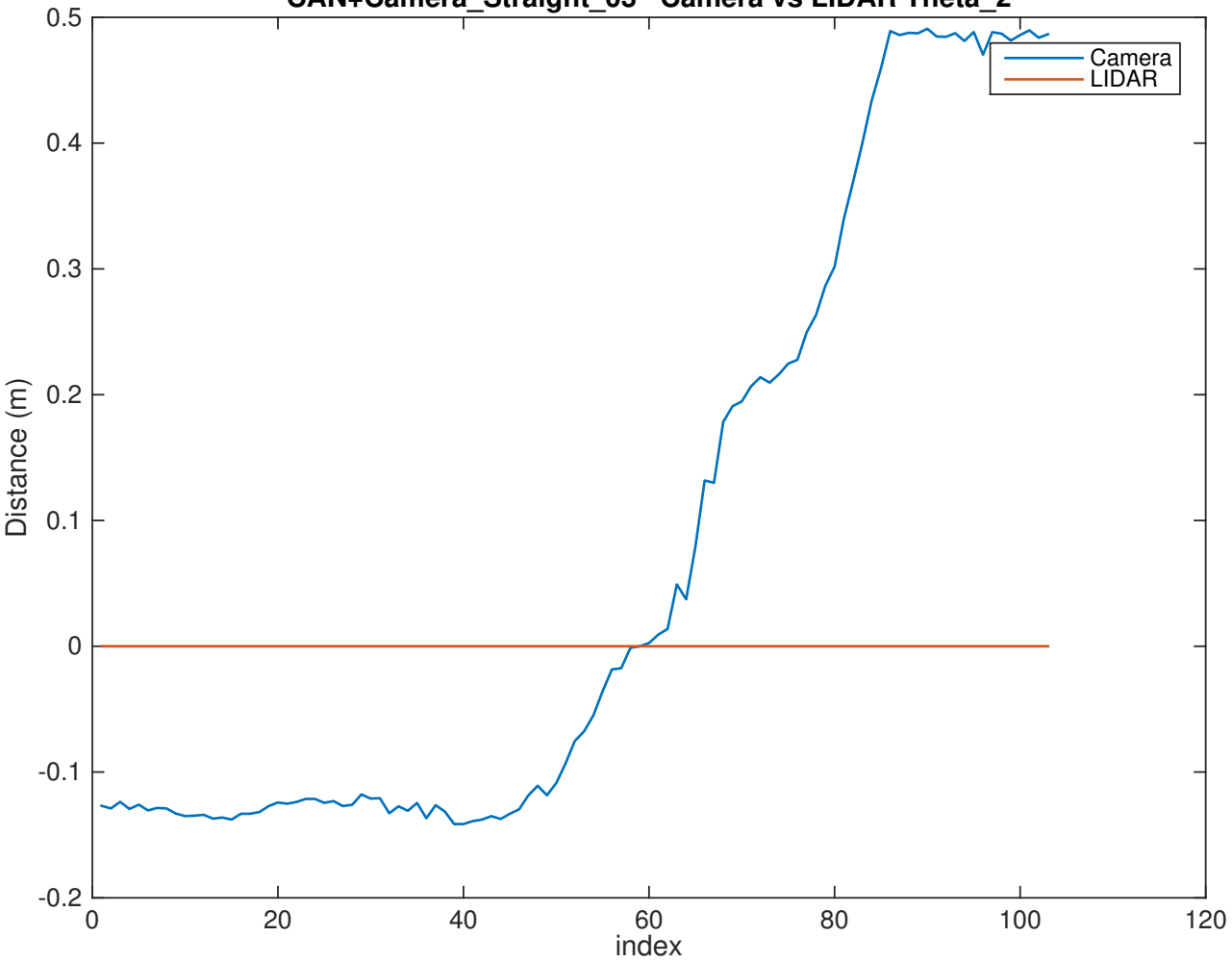
CAN+Camera_Straight_03 LIDAR Theta_1 vs Theta_2



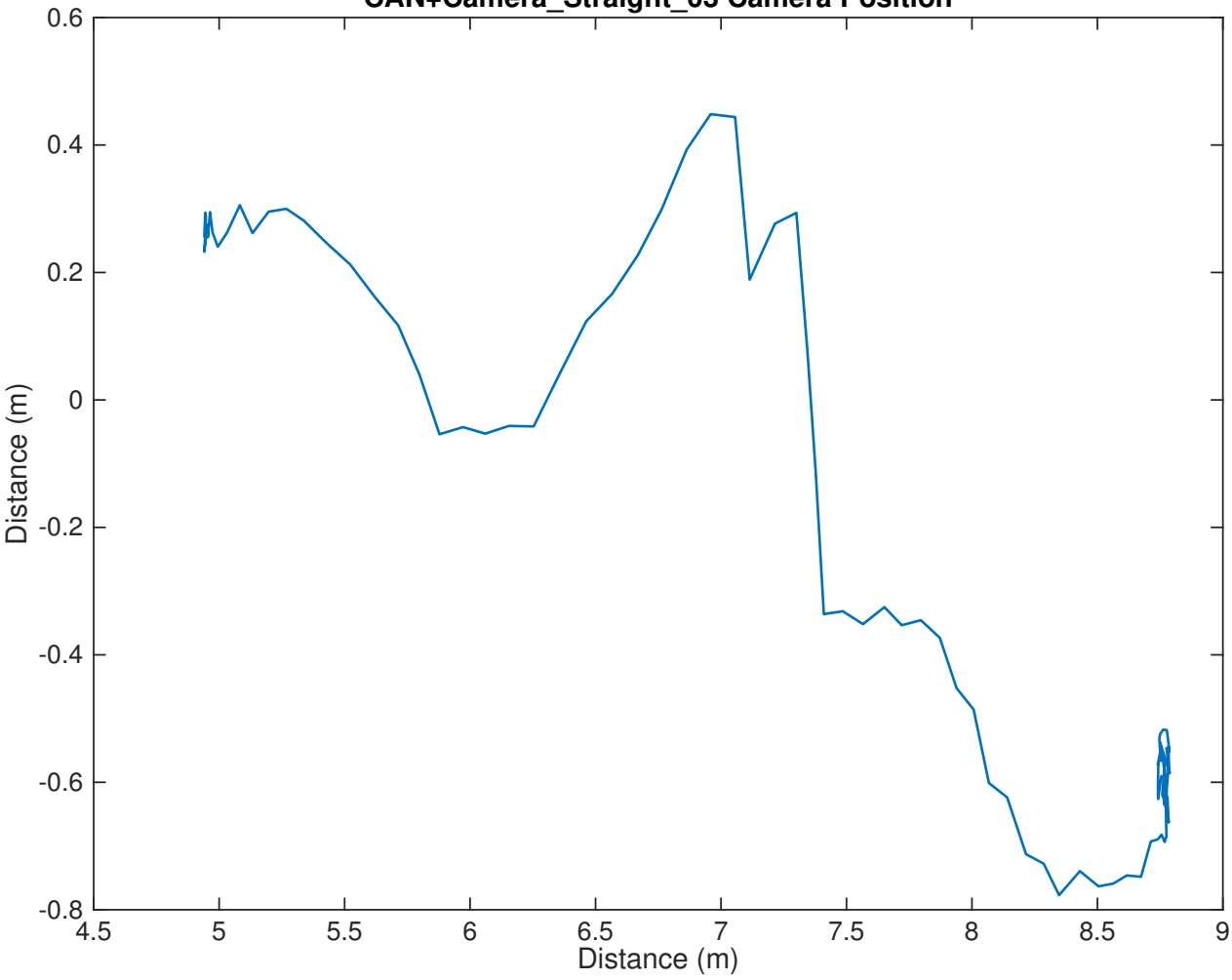
CAN+Camera_Straight_03 Camera vs LIDAR Theta_1



CAN+Camera_Straight_03 Camera vs LIDAR Theta_2

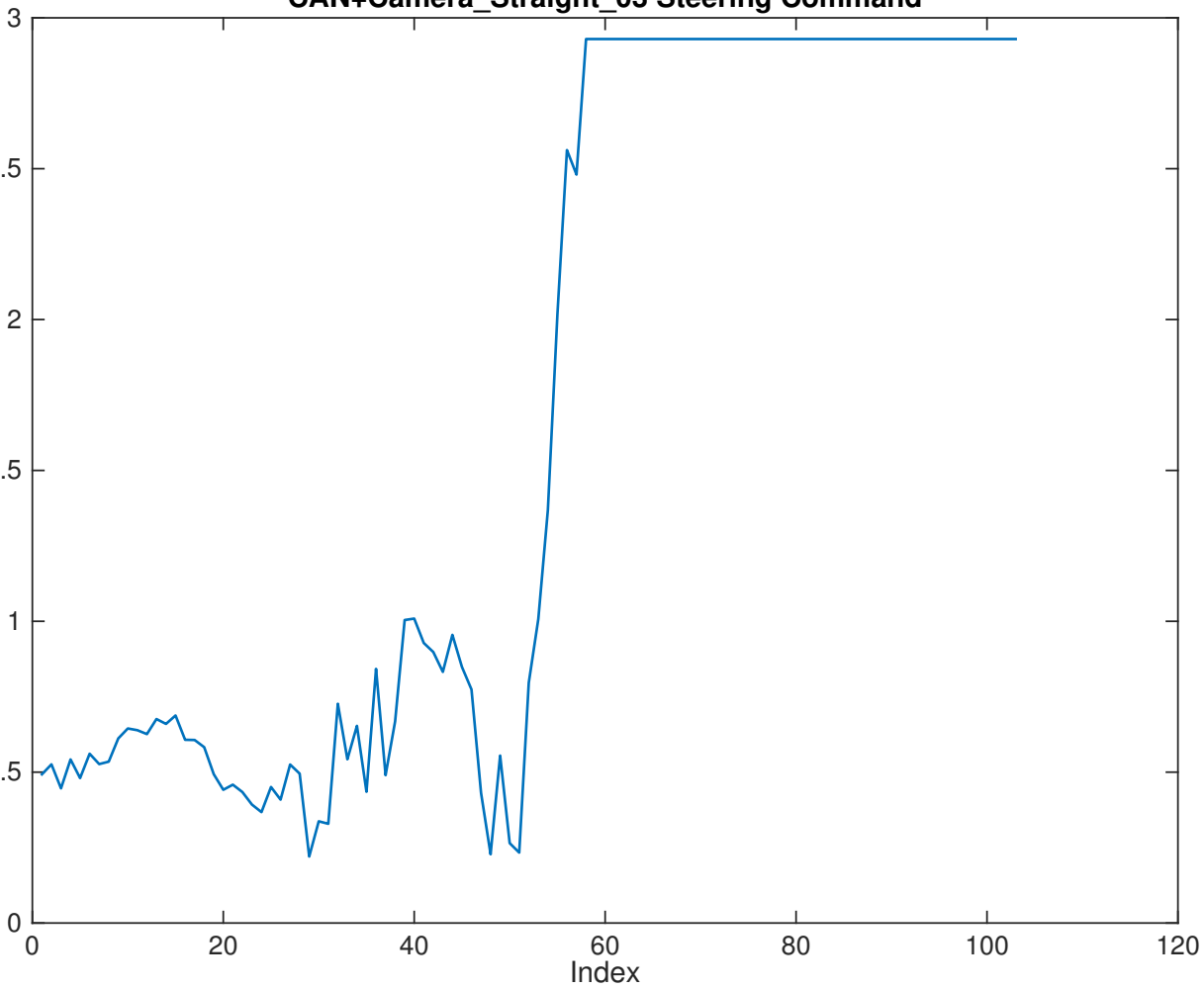


CAN+Camera_Straight_03 Camera Position

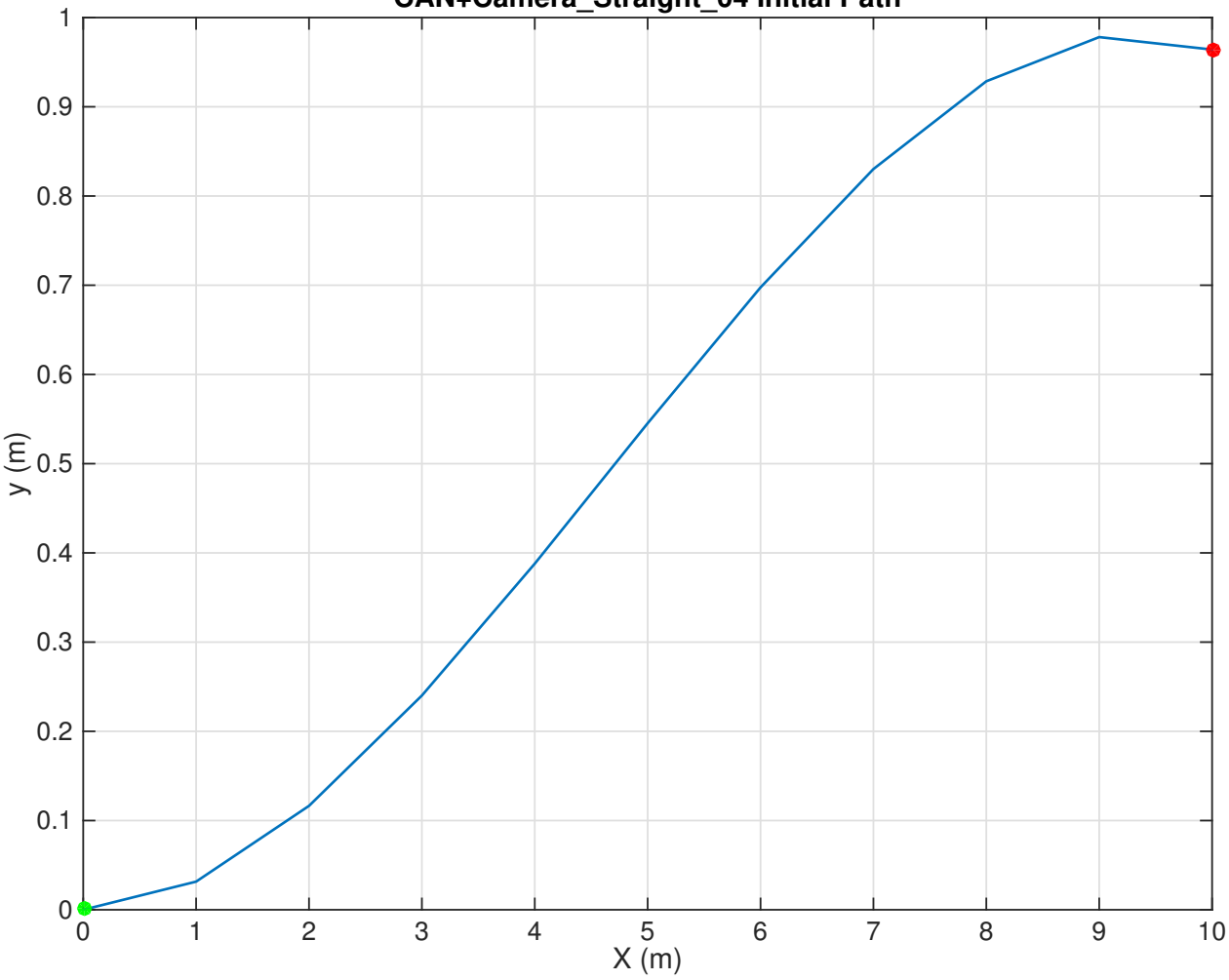


CAN+Camera_Straight_03 Steering Command

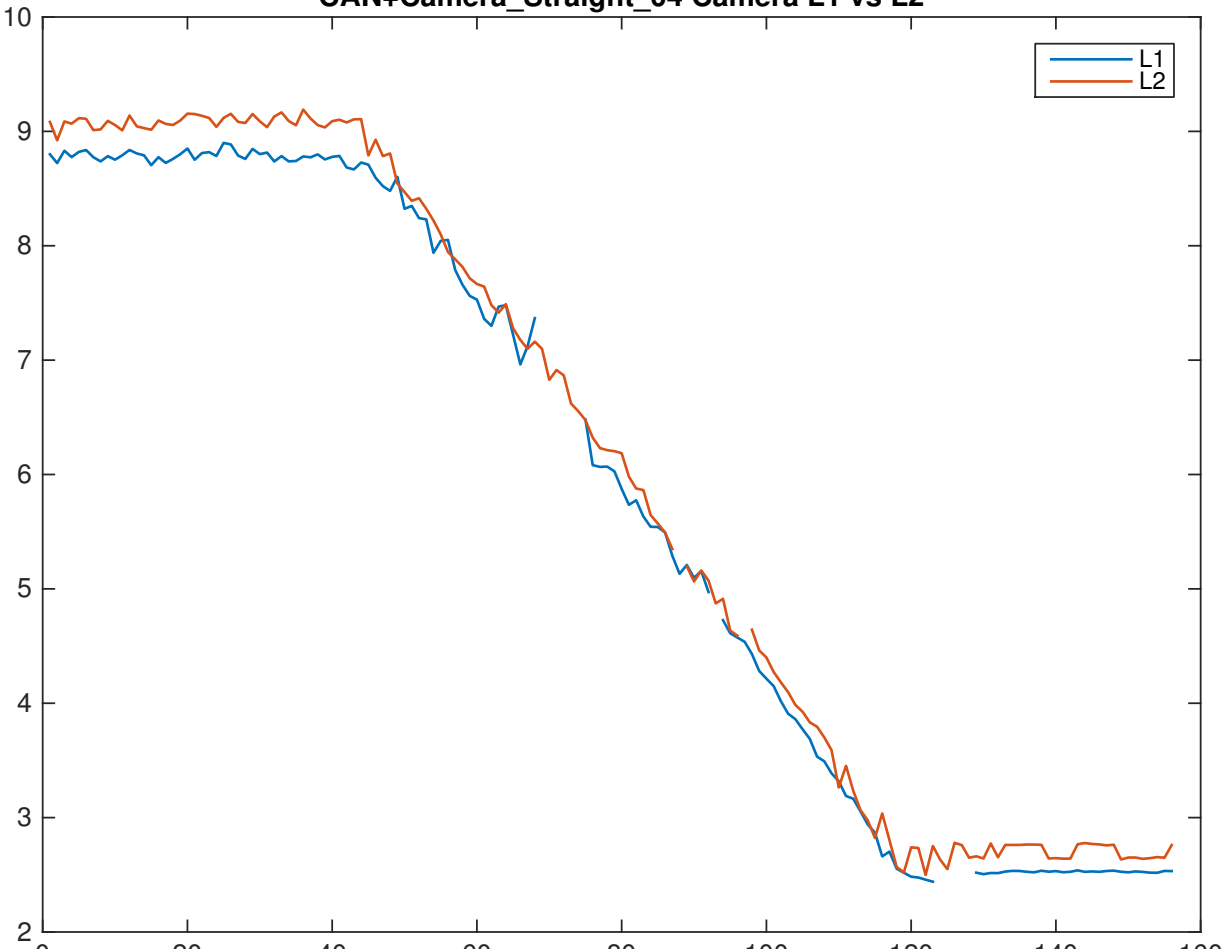
Turns (Clockwise Positive) 1 = 360° turn



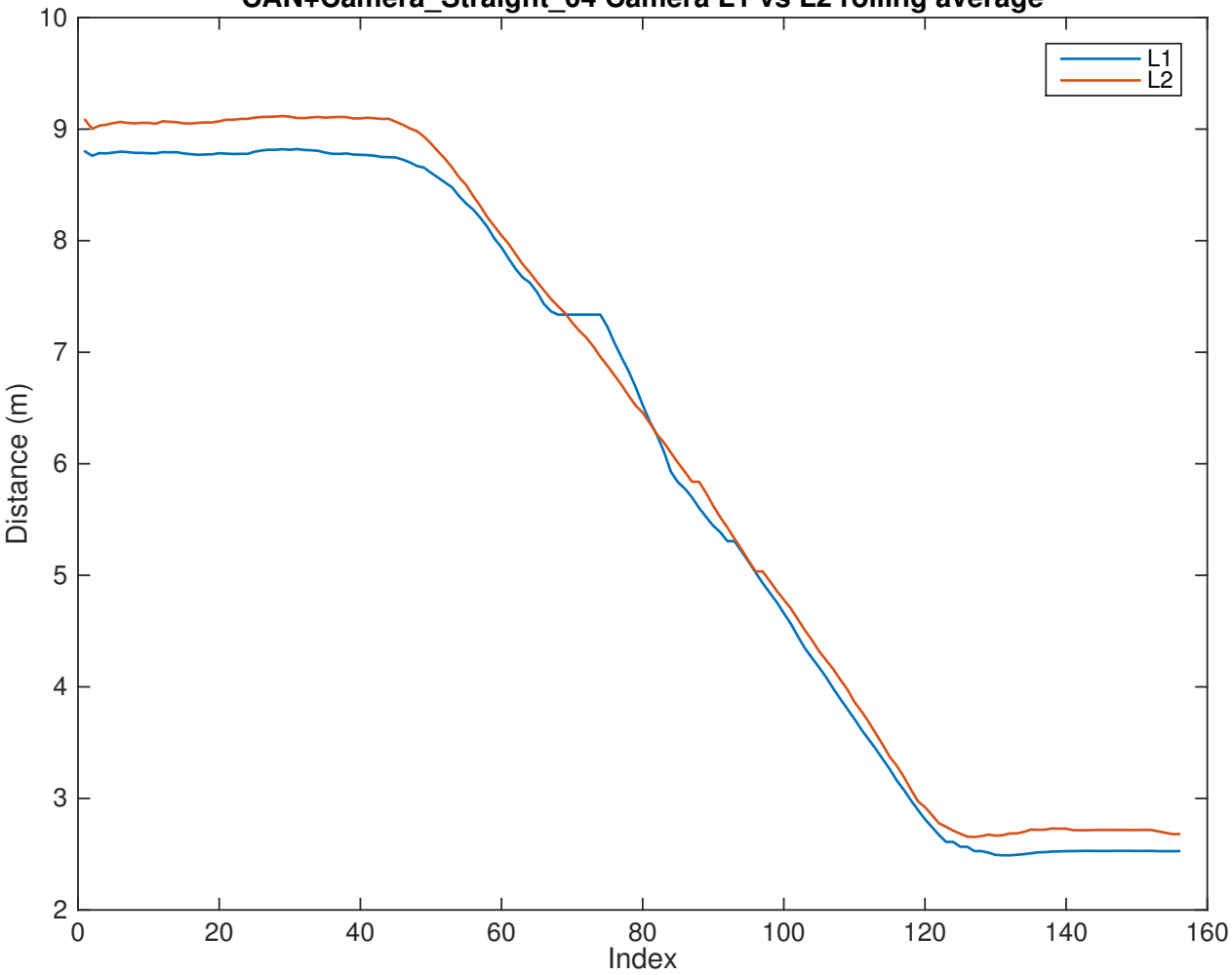
CAN+Camera_Straight_04 Initial Path



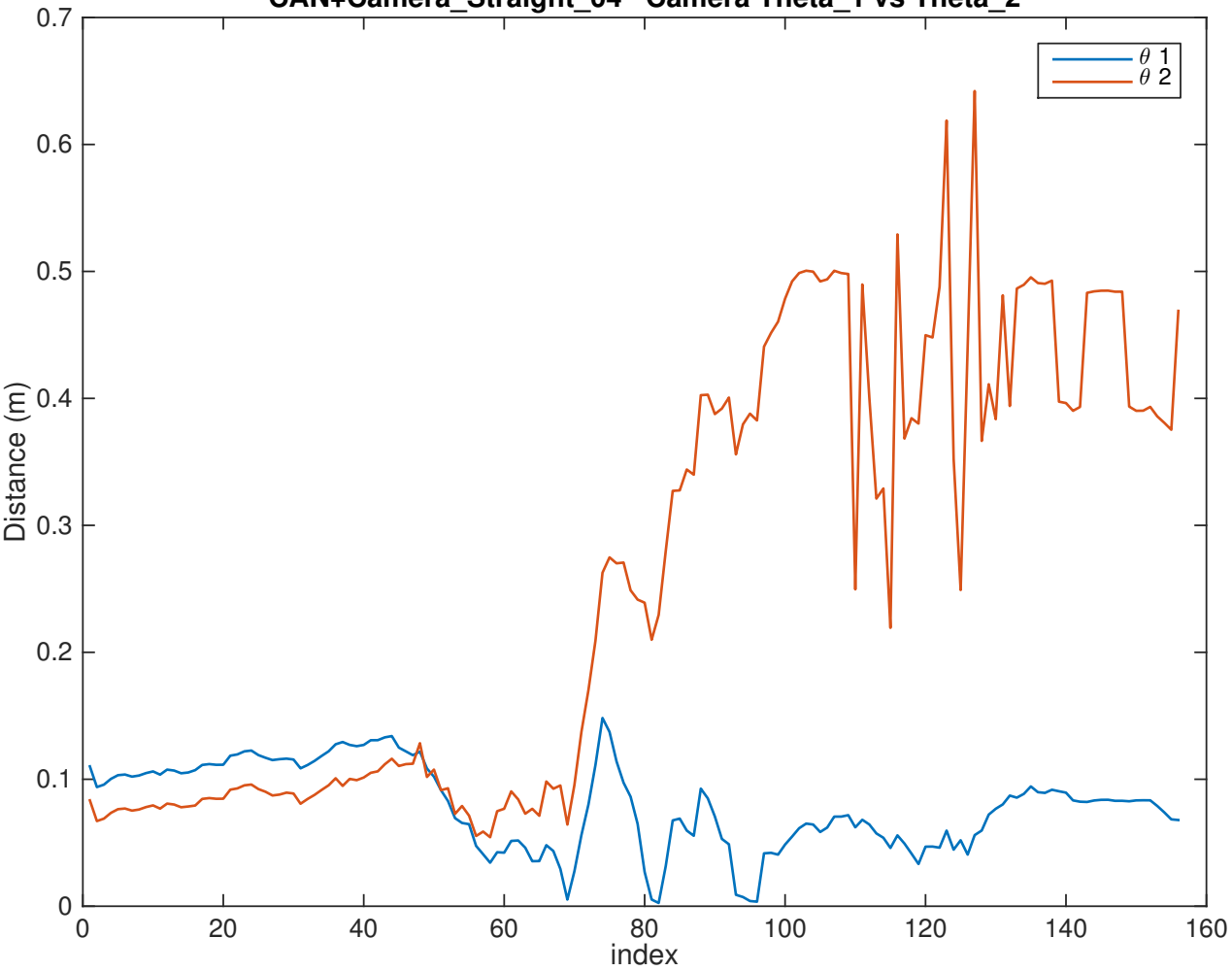
CAN+Camera_Straight_04 Camera L1 vs L2



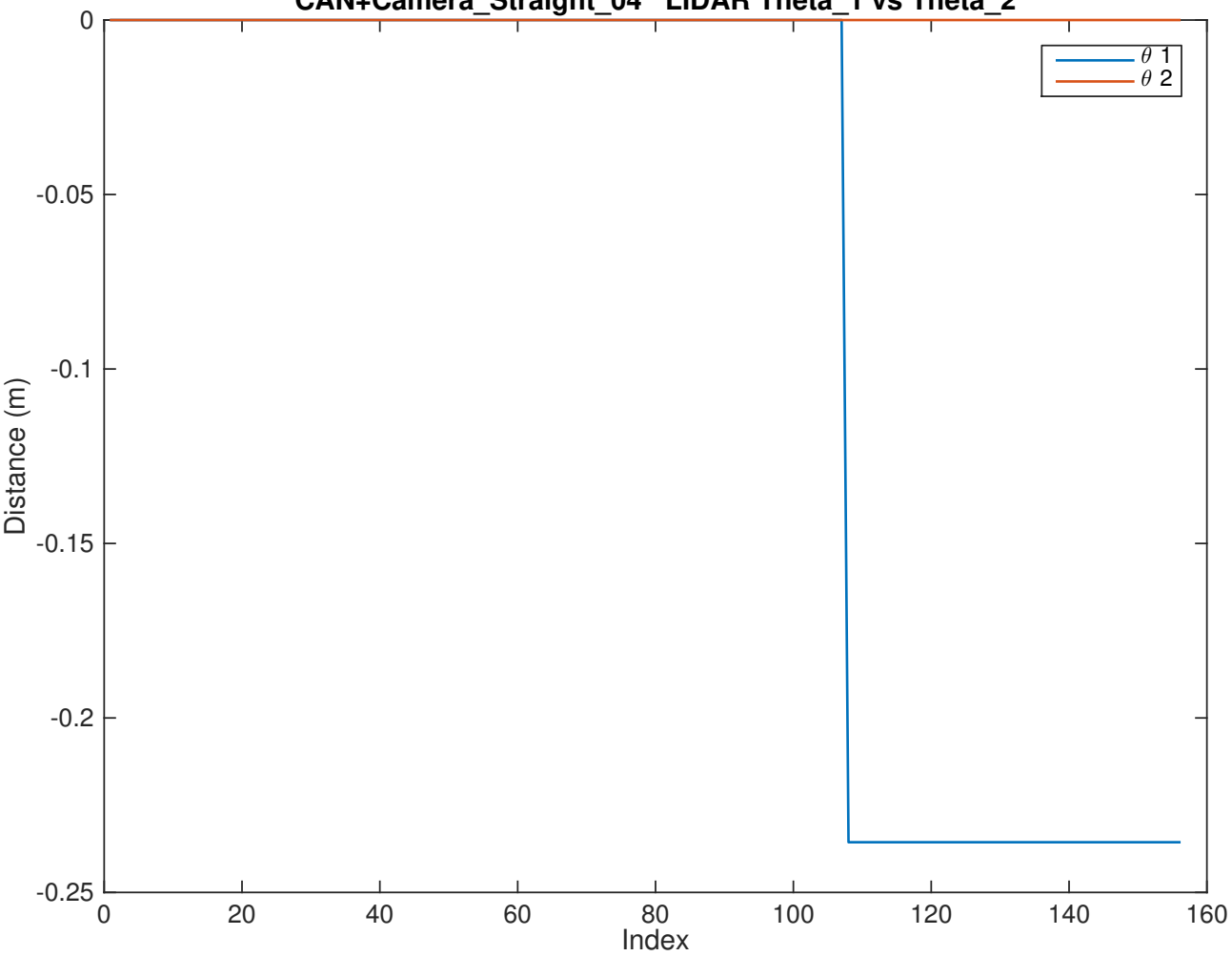
CAN+Camera_Straight_04 Camera L1 vs L2 rolling average



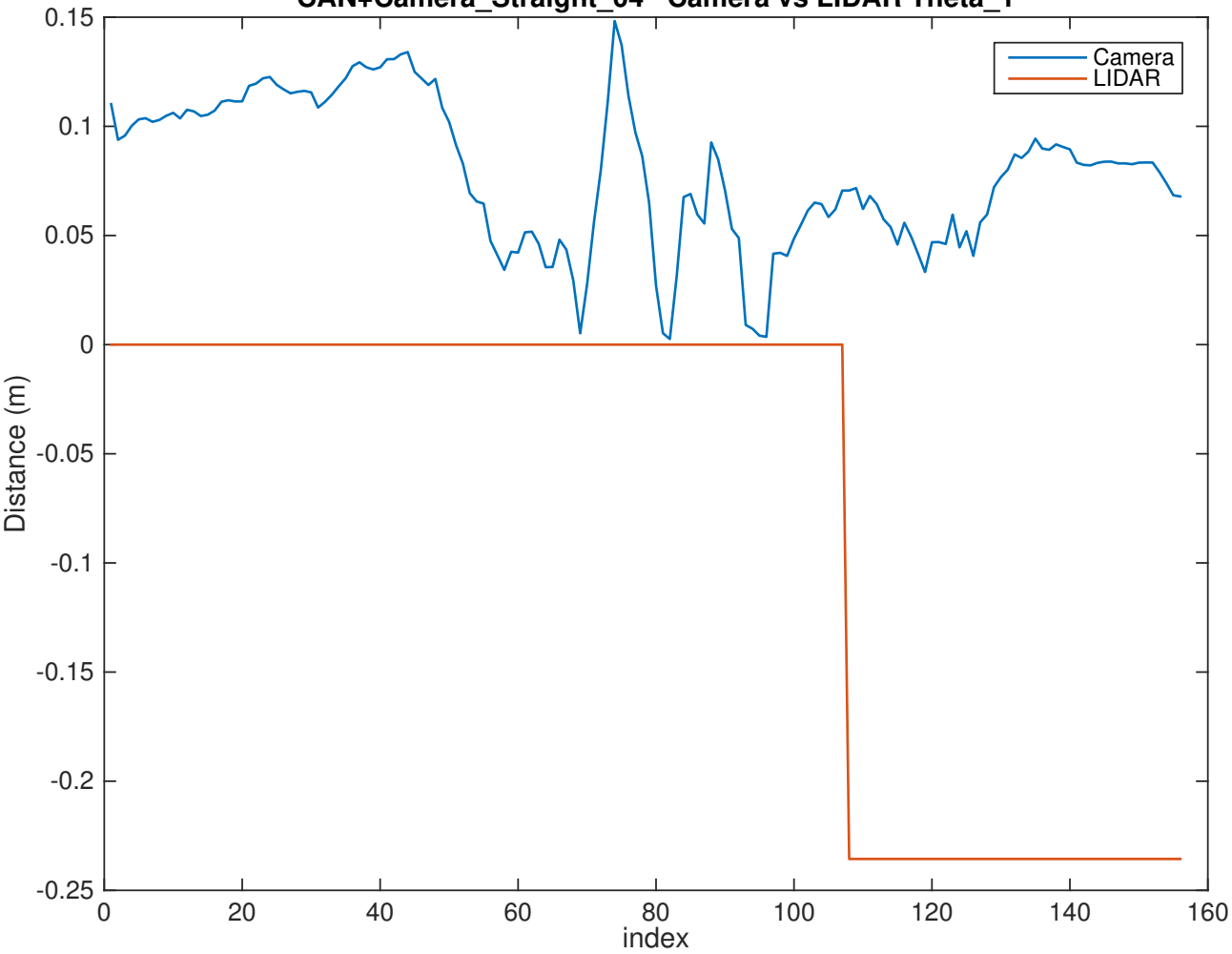
CAN+Camera_Straight_04 Camera Theta_1 vs Theta_2



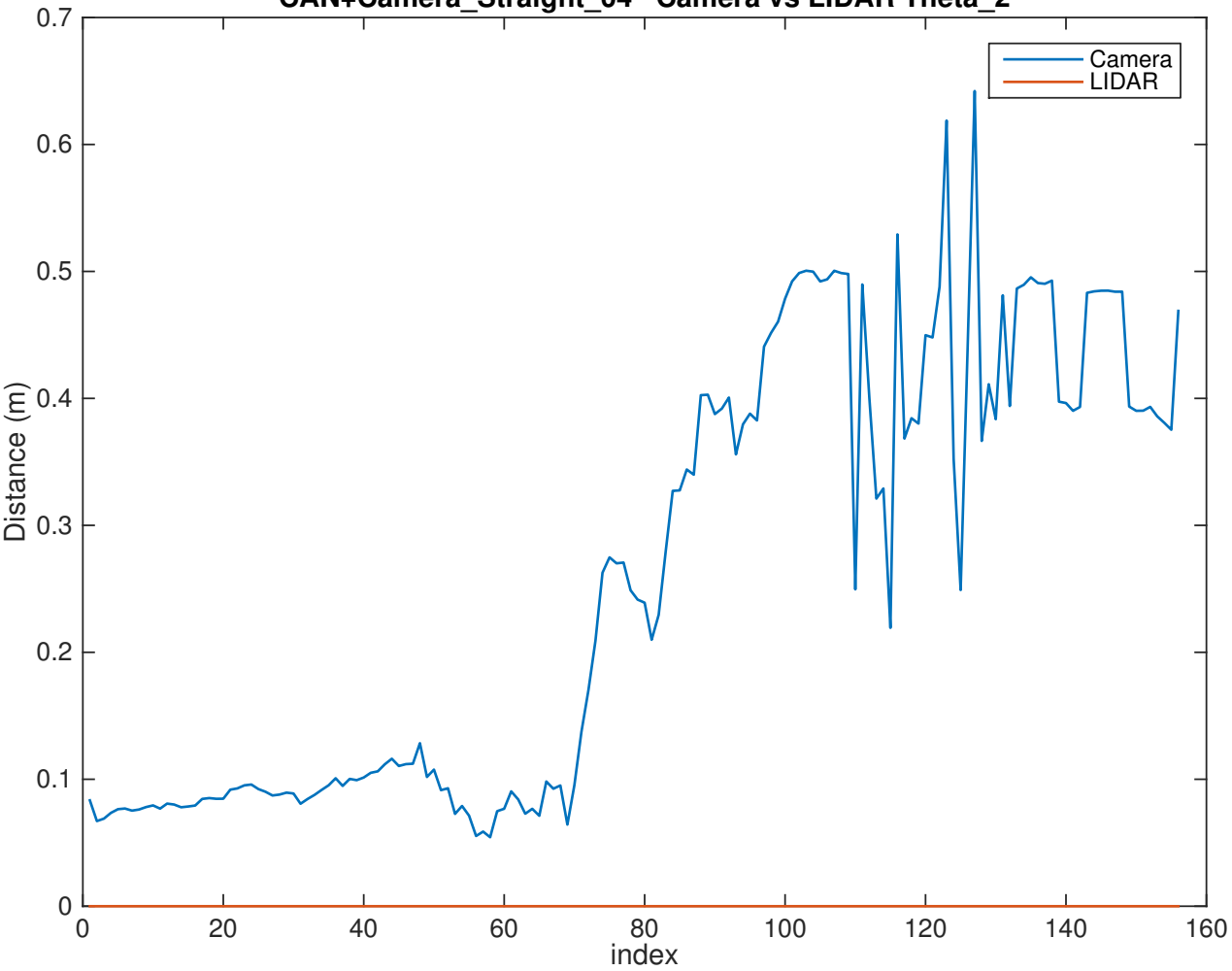
CAN+Camera_Straight_04 LIDAR Theta_1 vs Theta_2



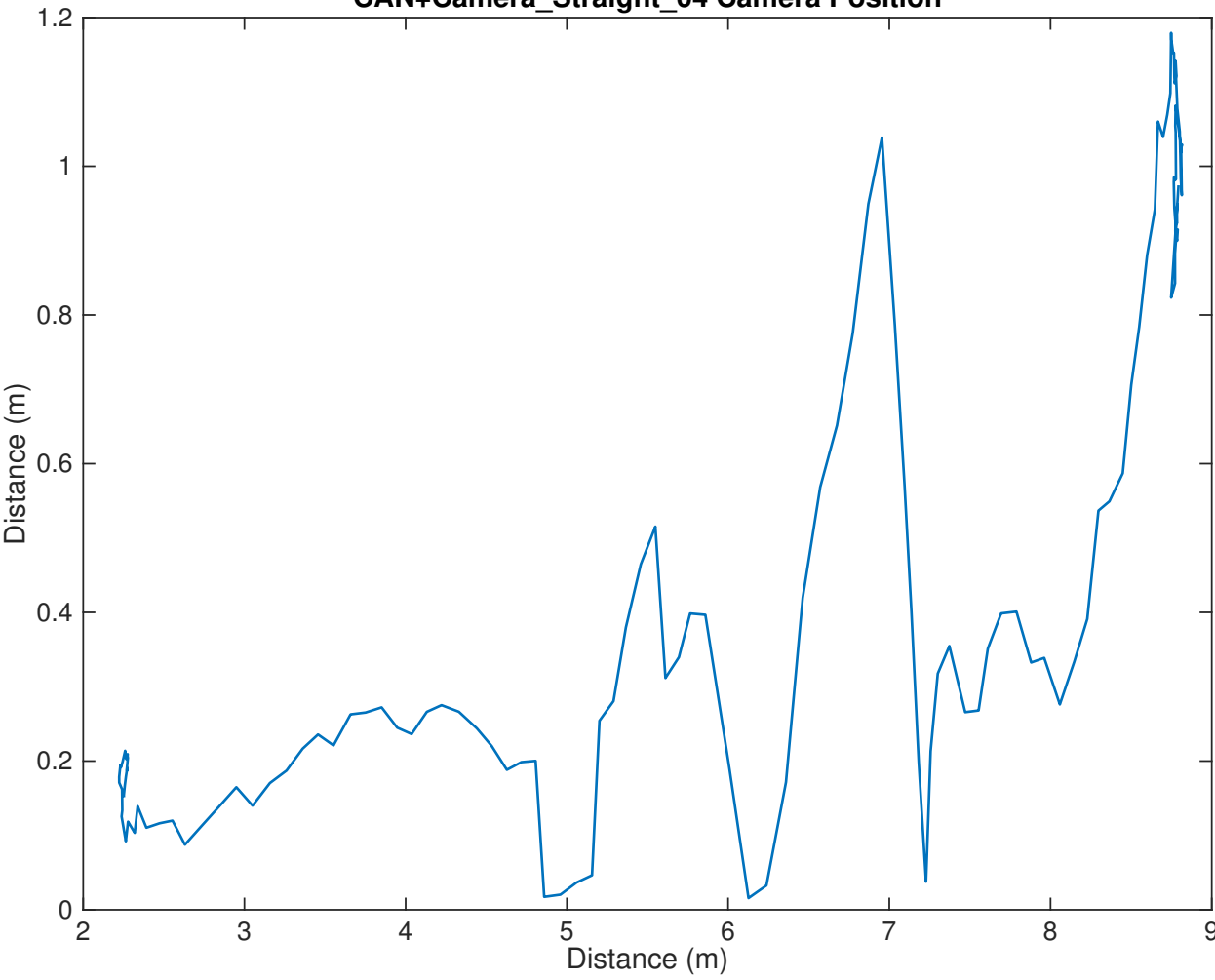
CAN+Camera_Straight_04 Camera vs LIDAR Theta_1



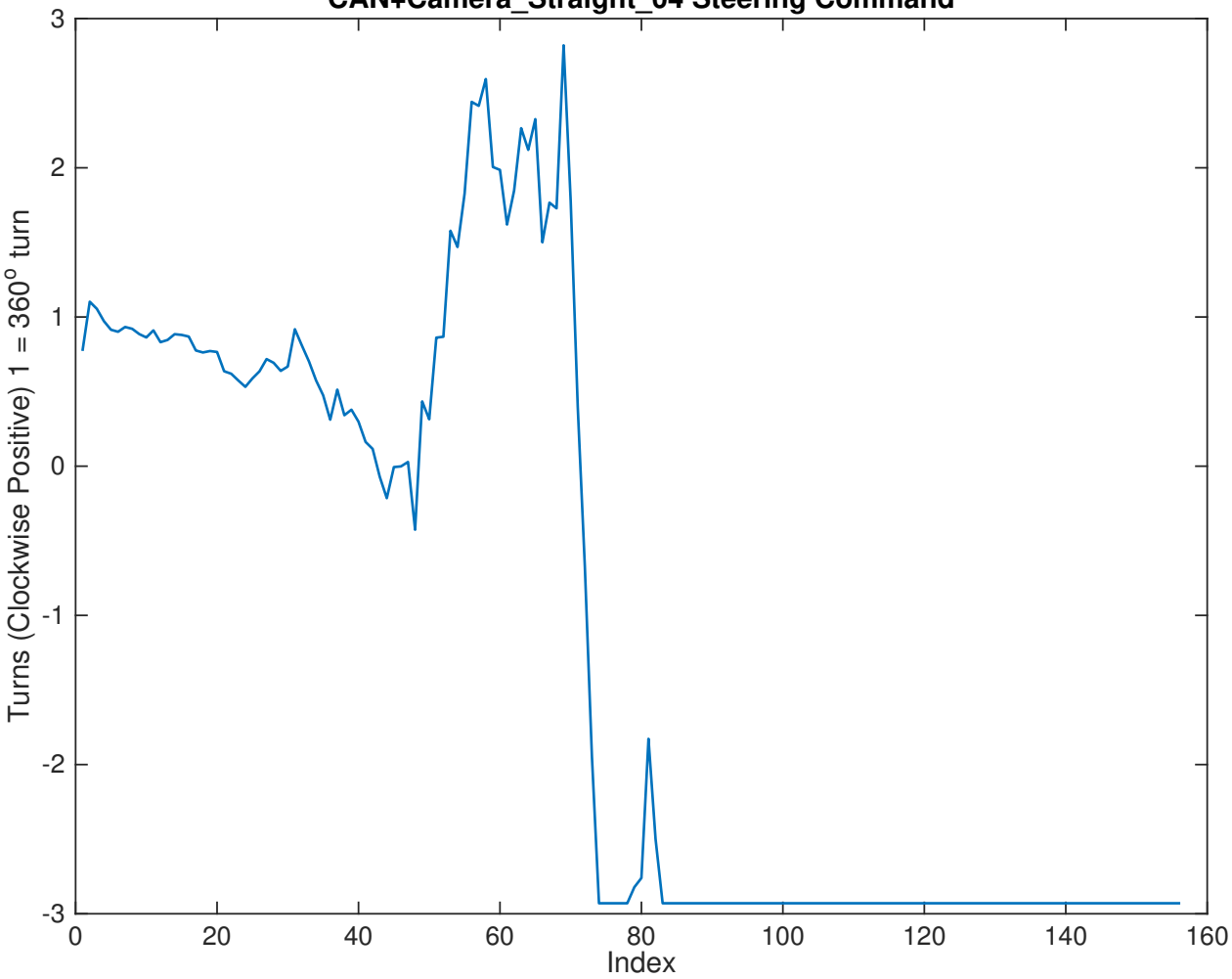
CAN+Camera_Straight_04 Camera vs LIDAR Theta_2



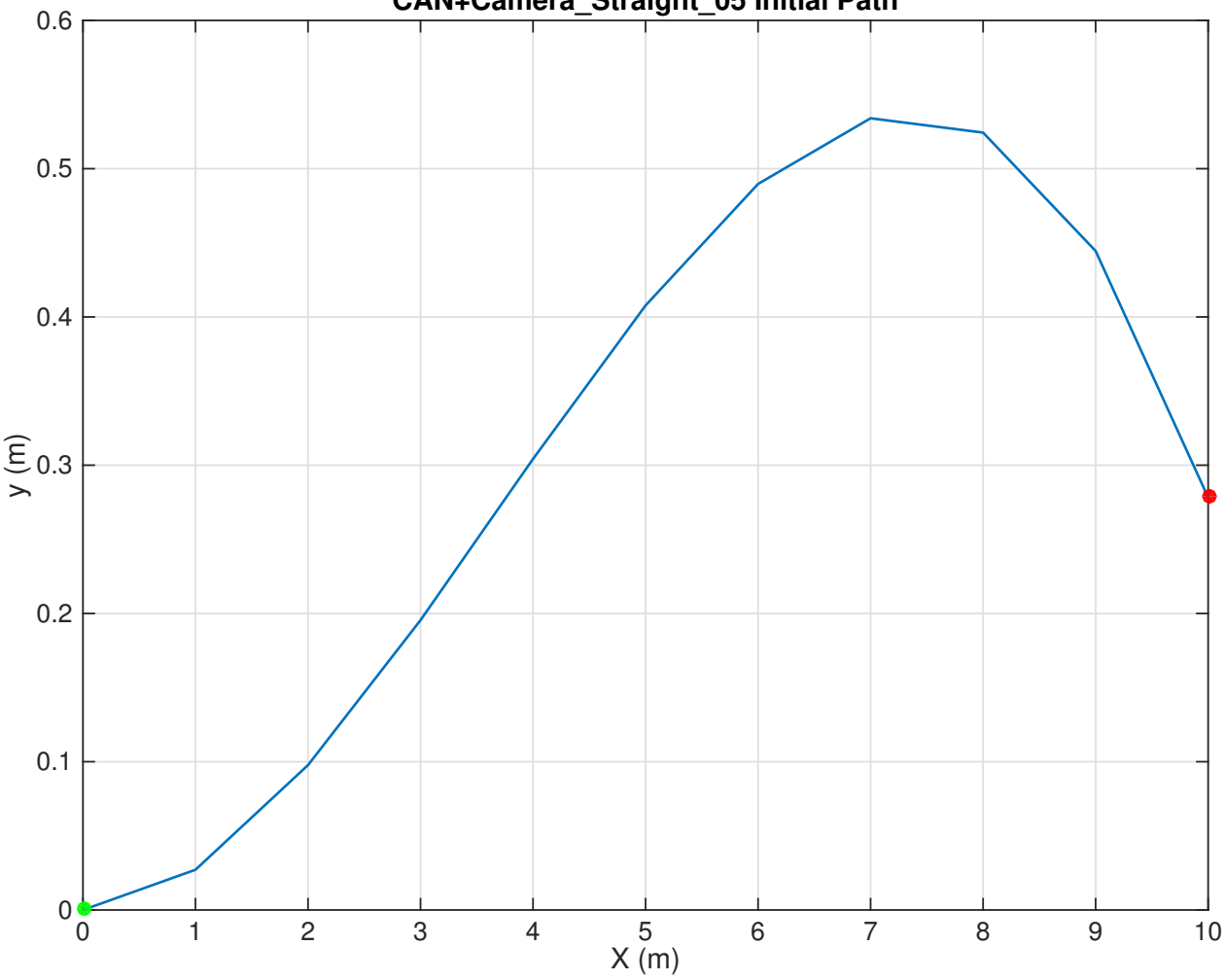
CAN+Camera_Straight_04 Camera Position



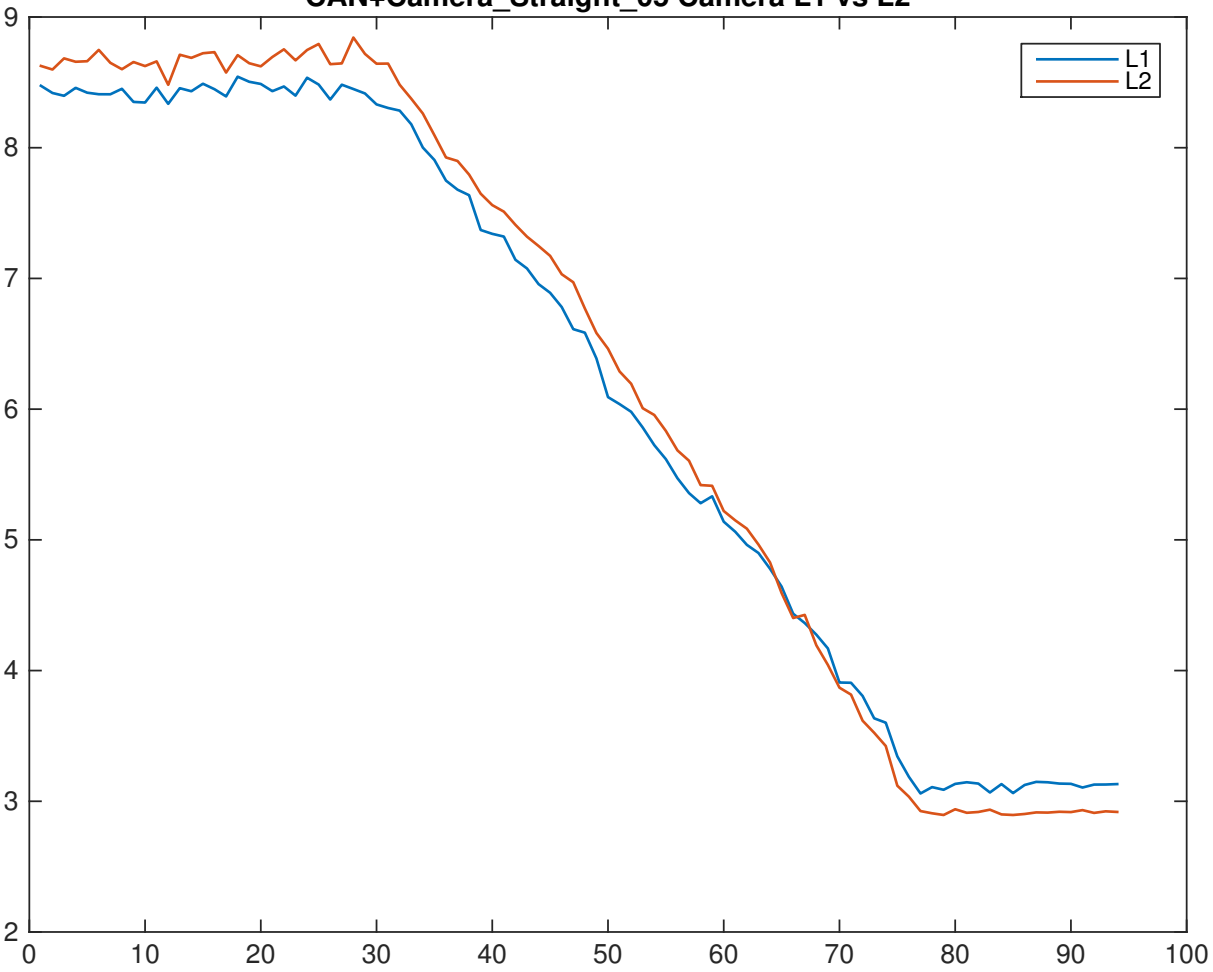
CAN+Camera_Straight_04 Steering Command



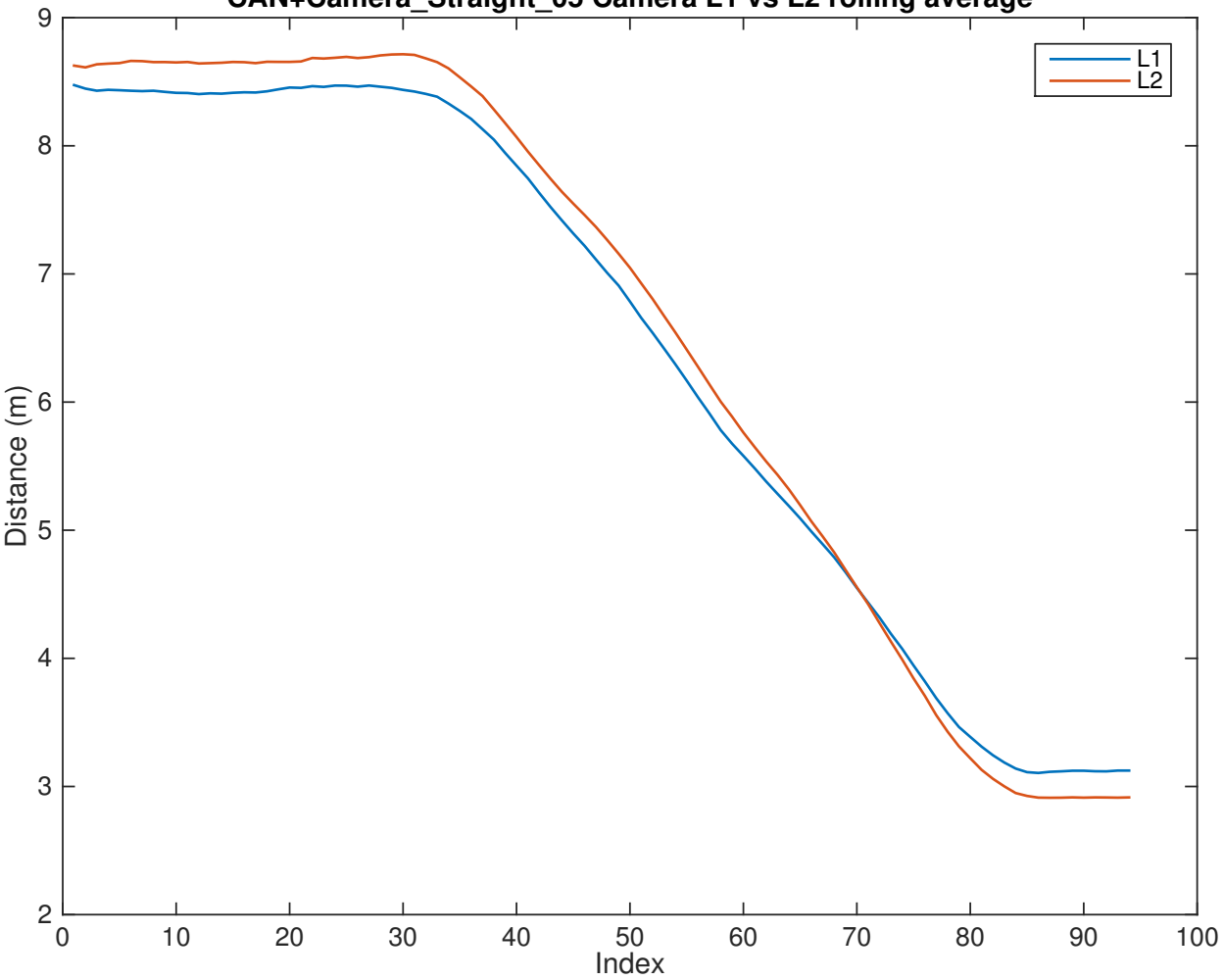
CAN+Camera_Straight_05 Initial Path



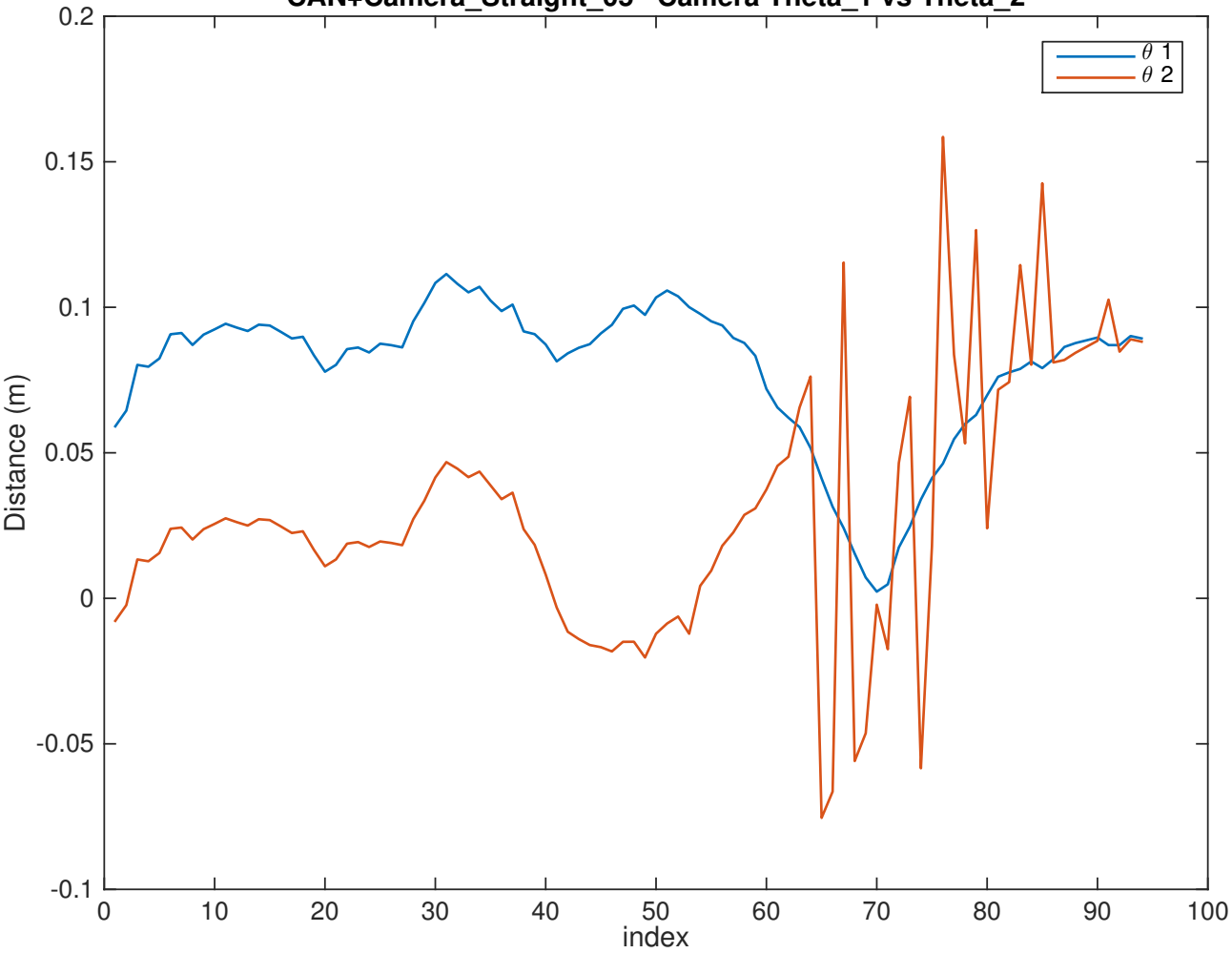
CAN+Camera_Straight_05 Camera L1 vs L2



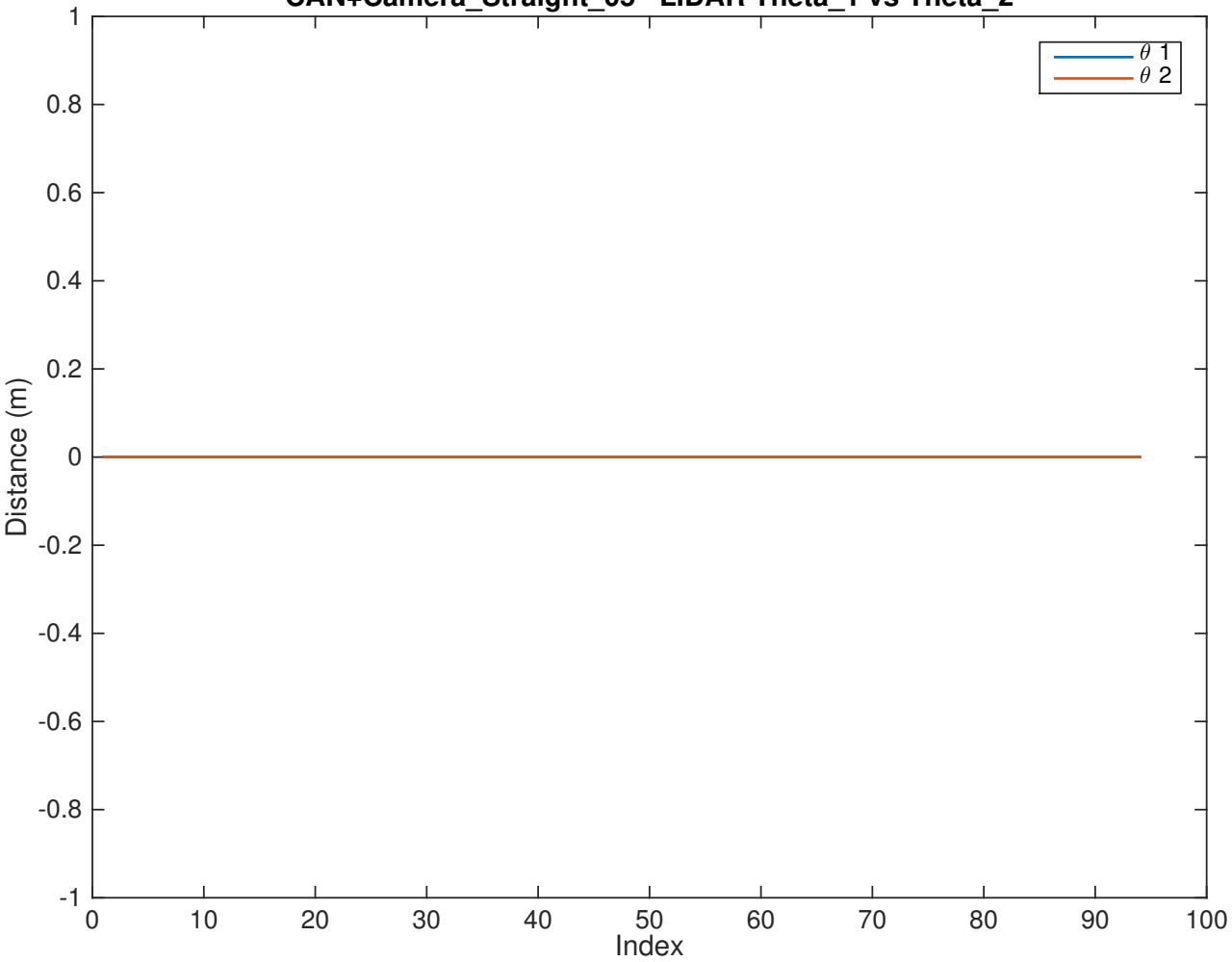
CAN+Camera_Straight_05 Camera L1 vs L2 rolling average



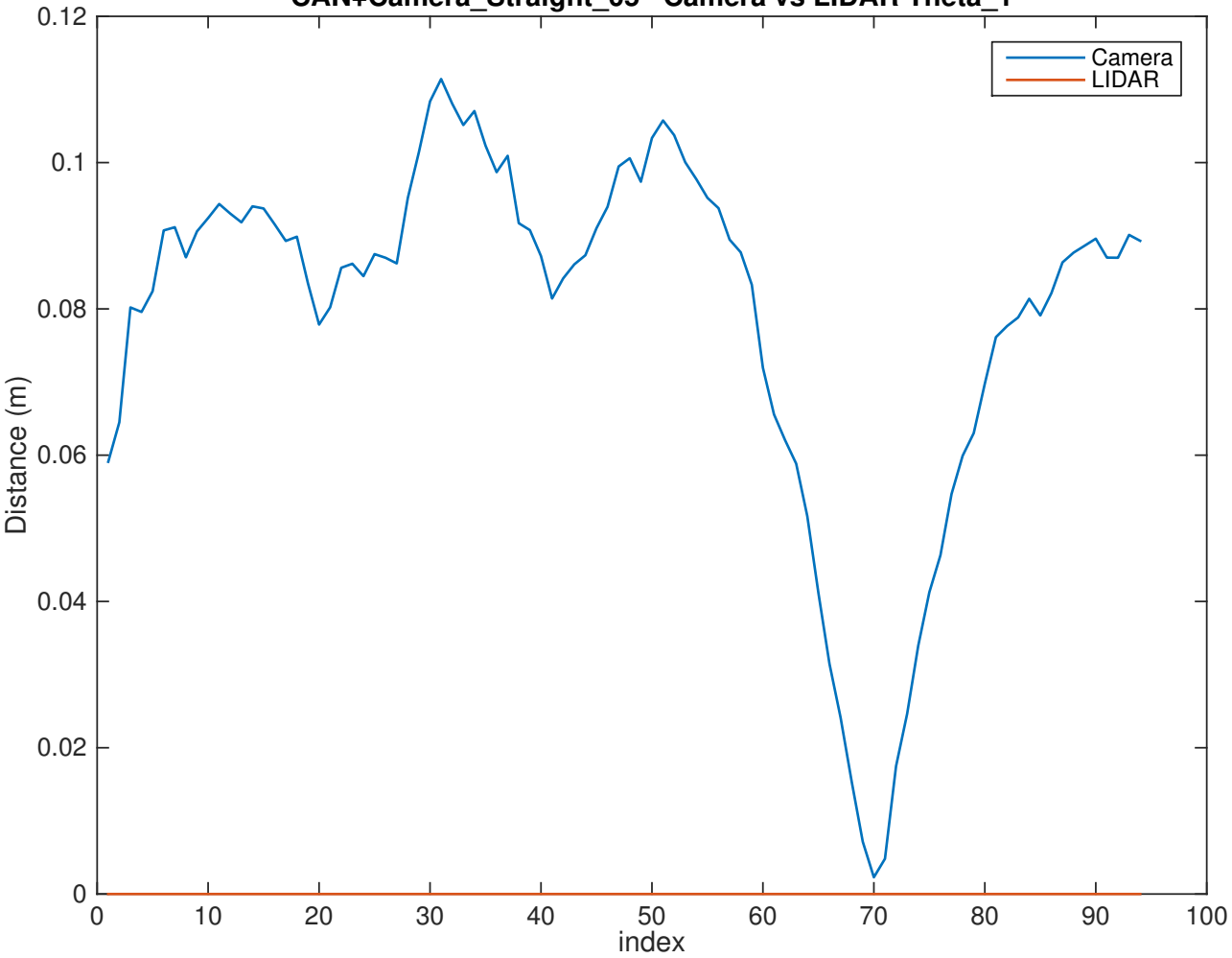
CAN+Camera_Straight_05 Camera Theta_1 vs Theta_2



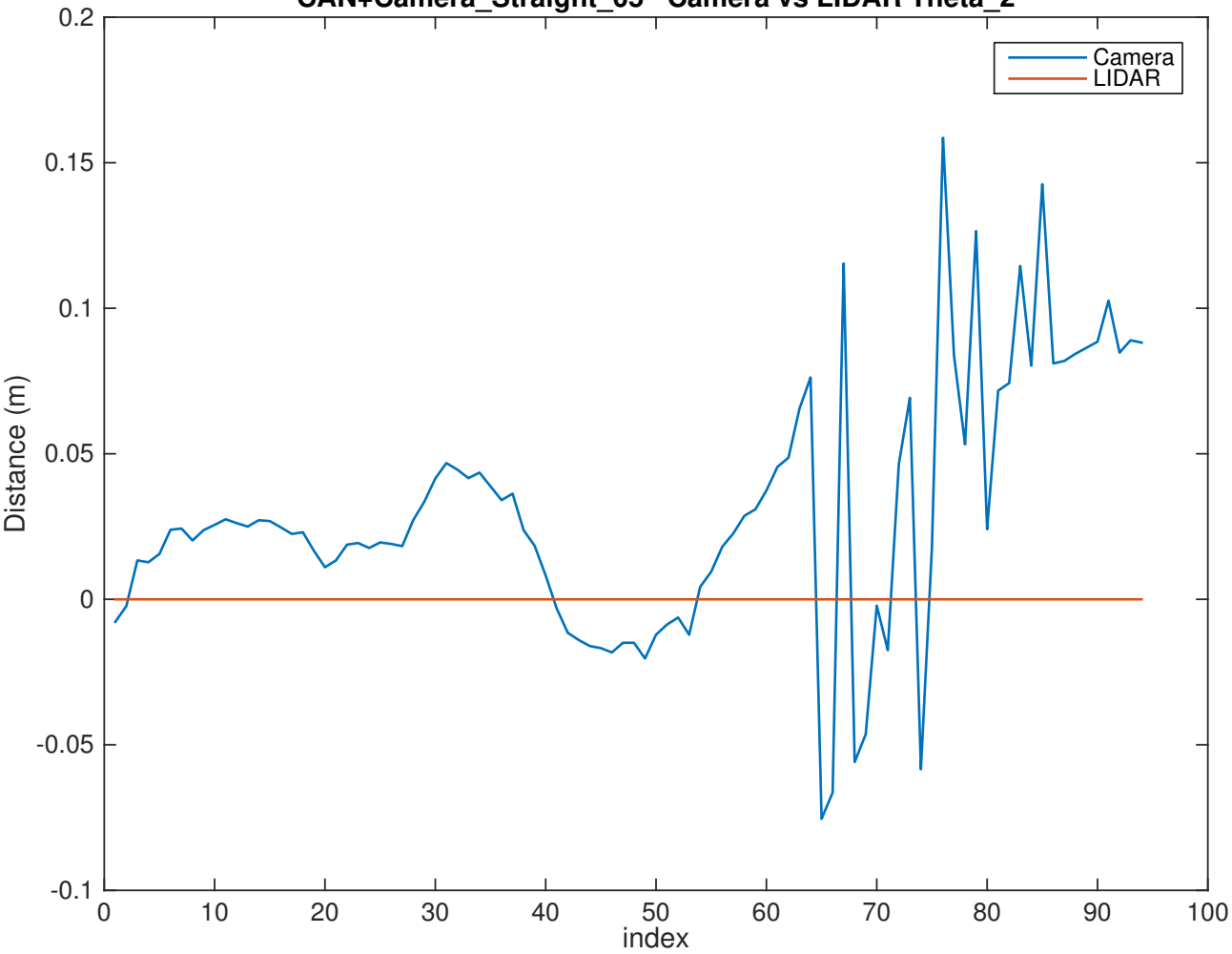
CAN+Camera_Straight_05 LIDAR Theta_1 vs Theta_2



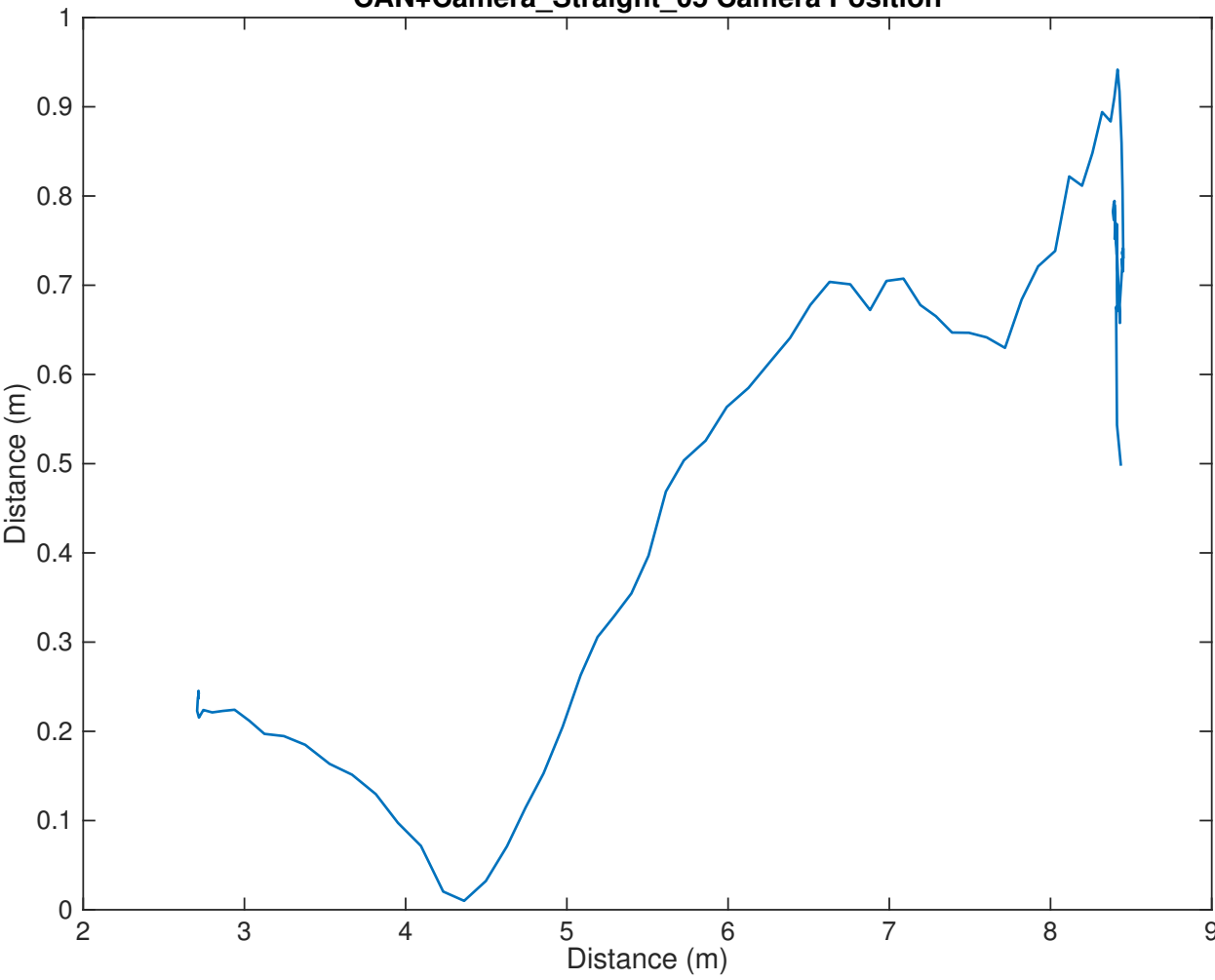
CAN+Camera_Straight_05 Camera vs LIDAR Theta_1



CAN+Camera_Straight_05 Camera vs LIDAR Theta_2



CAN+Camera_Straight_05 Camera Position



CAN+Camera_Straight_05 Steering Command

