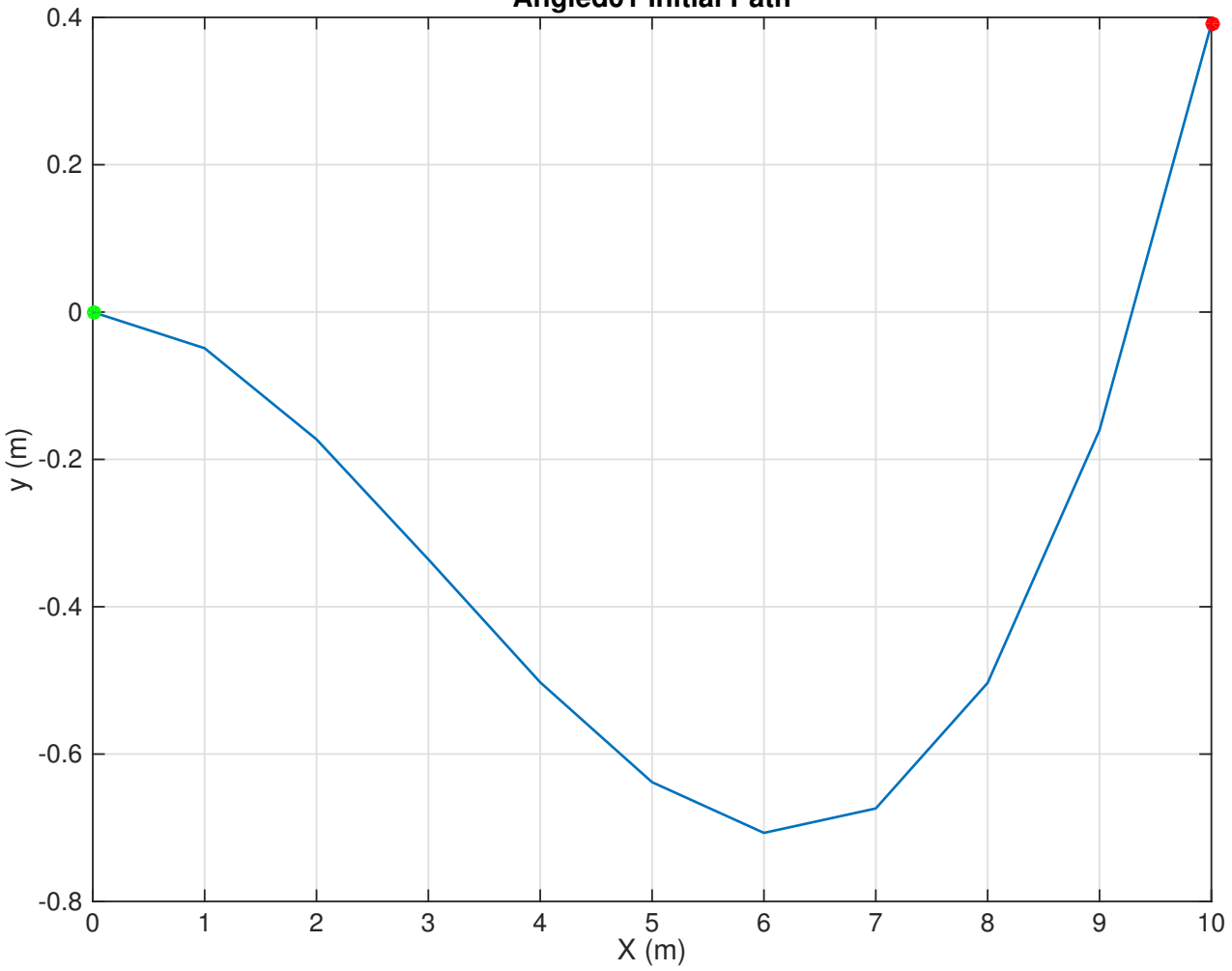
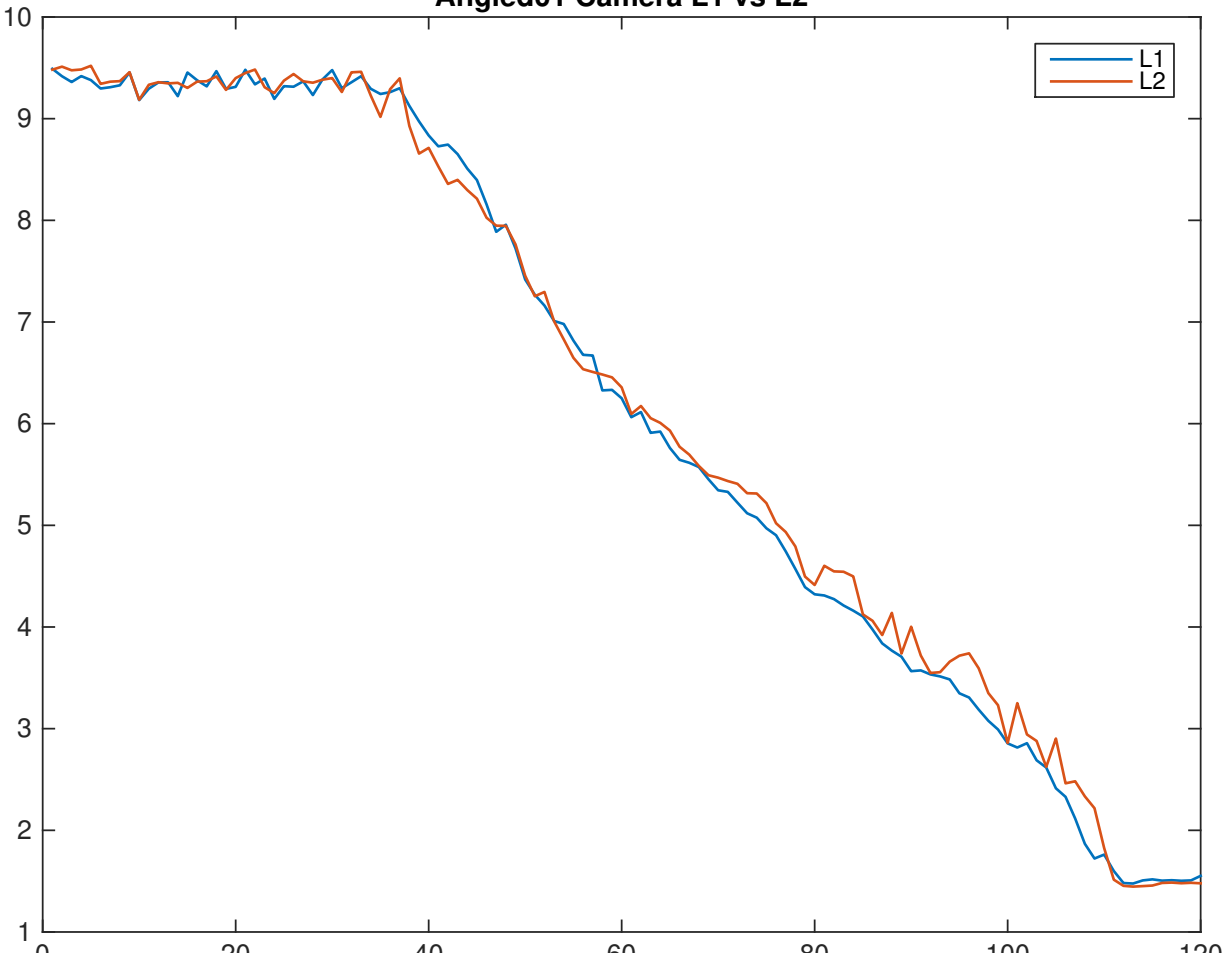


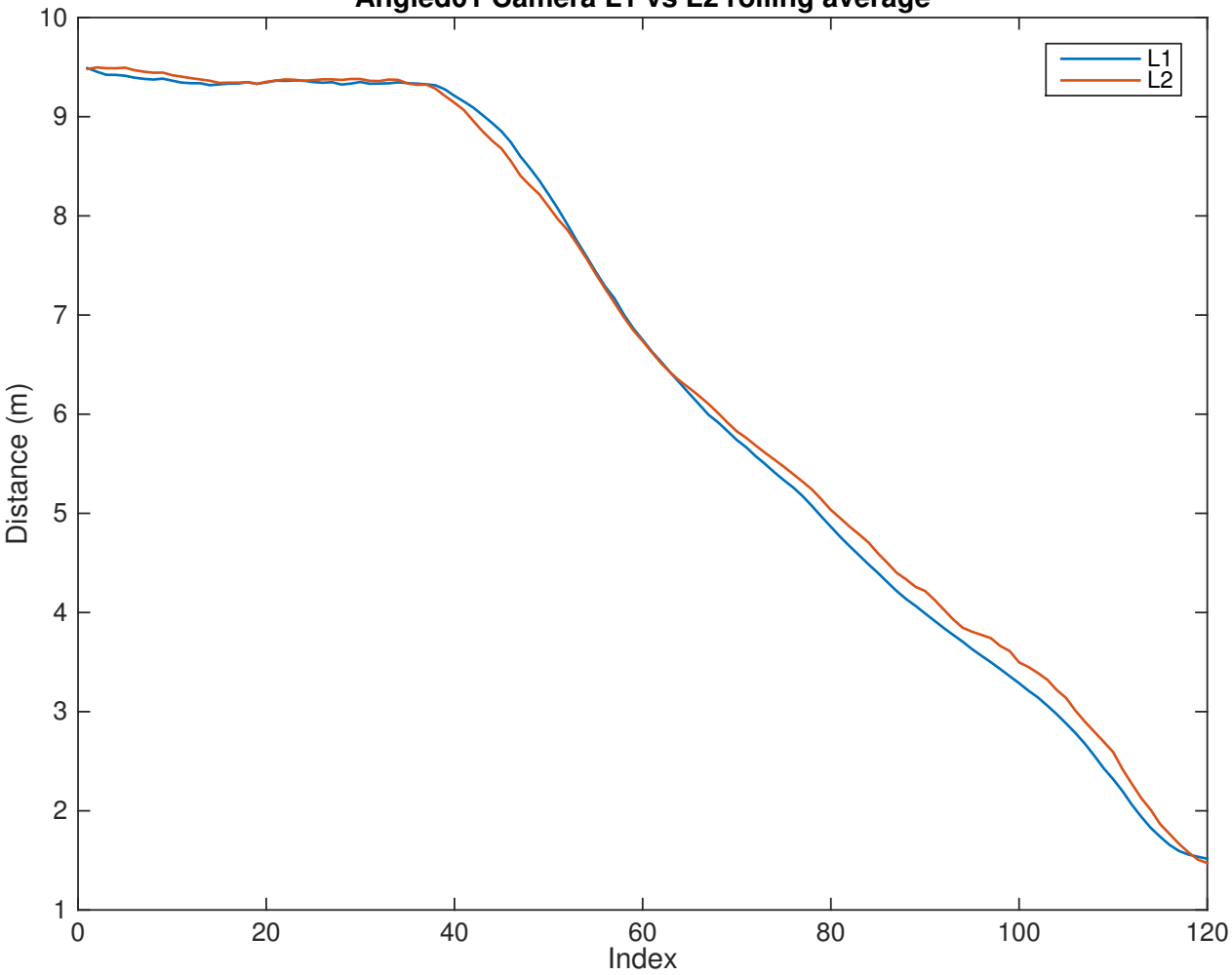
Angled01 Initial Path



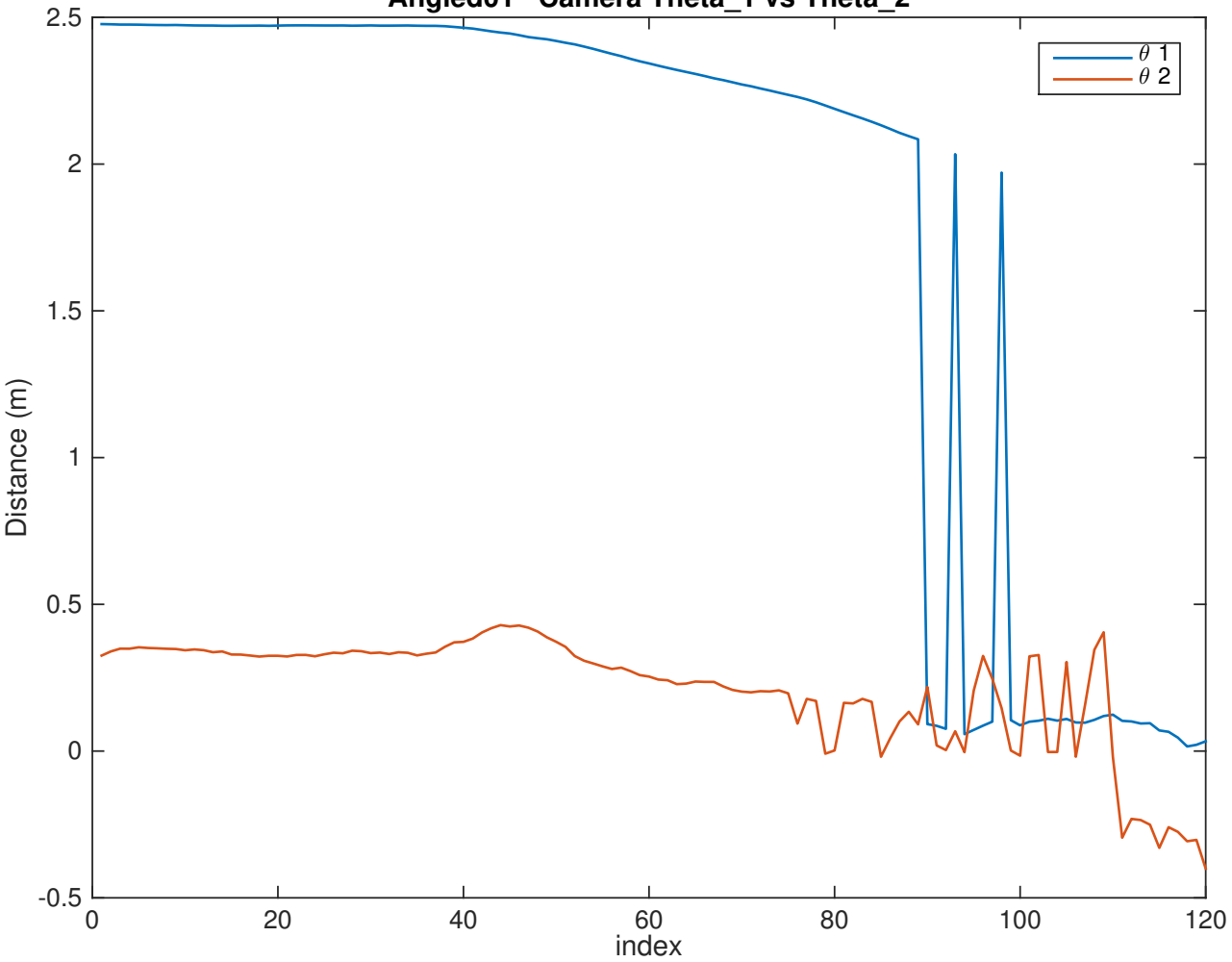
Angled01 Camera L1 vs L2



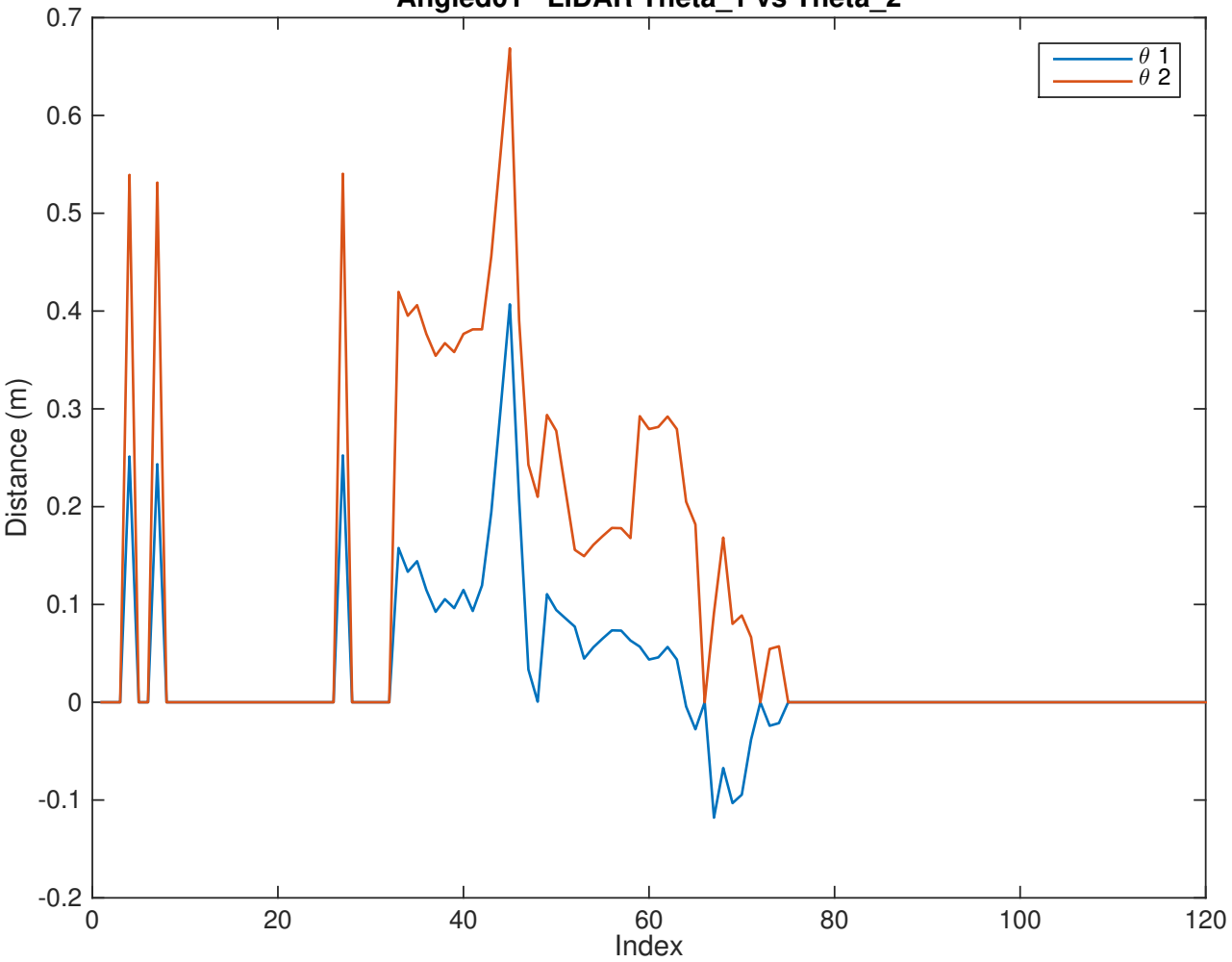
Angled01 Camera L1 vs L2 rolling average



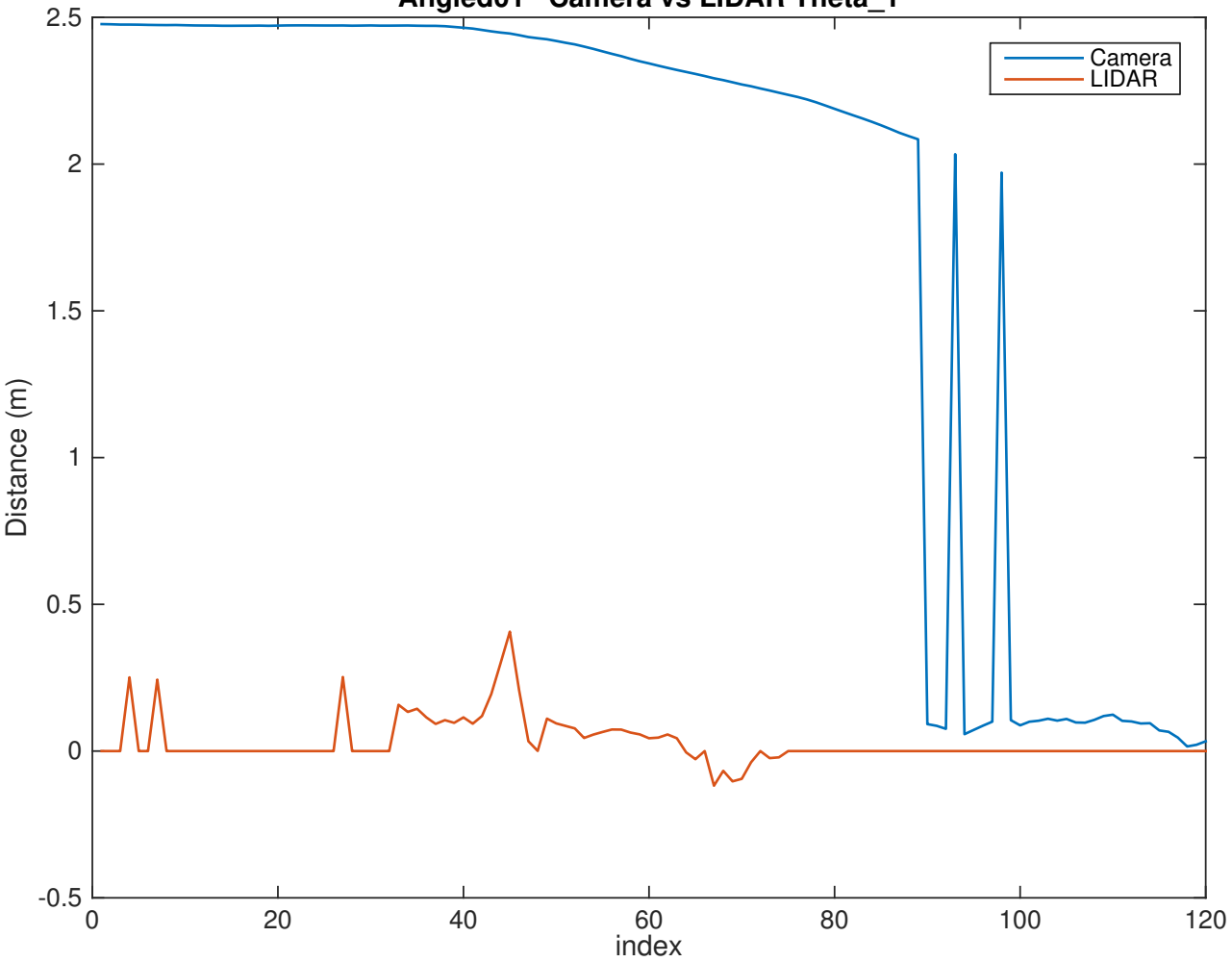
Angled01 Camera Theta_1 vs Theta_2



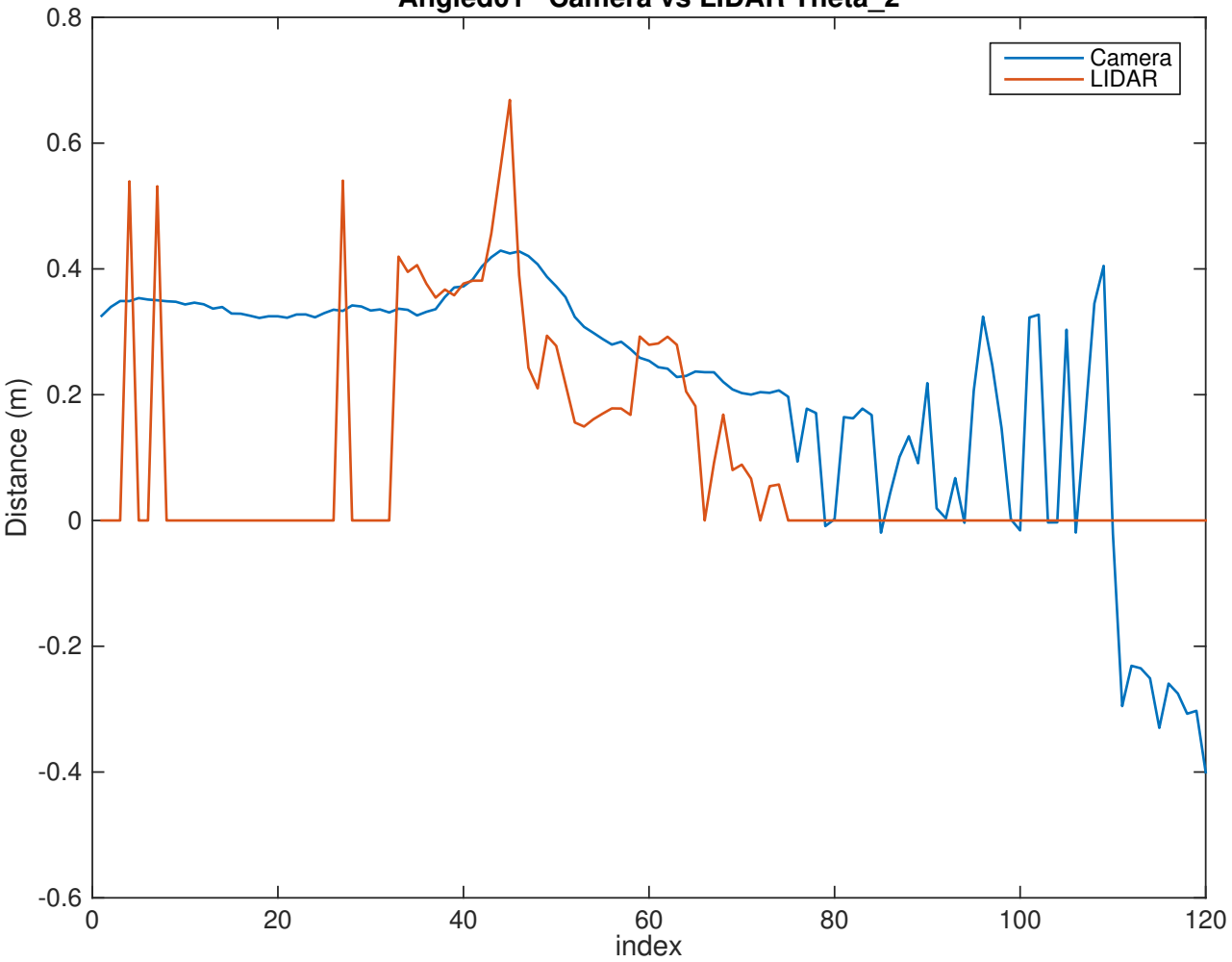
Angled01 LIDAR Theta_1 vs Theta_2



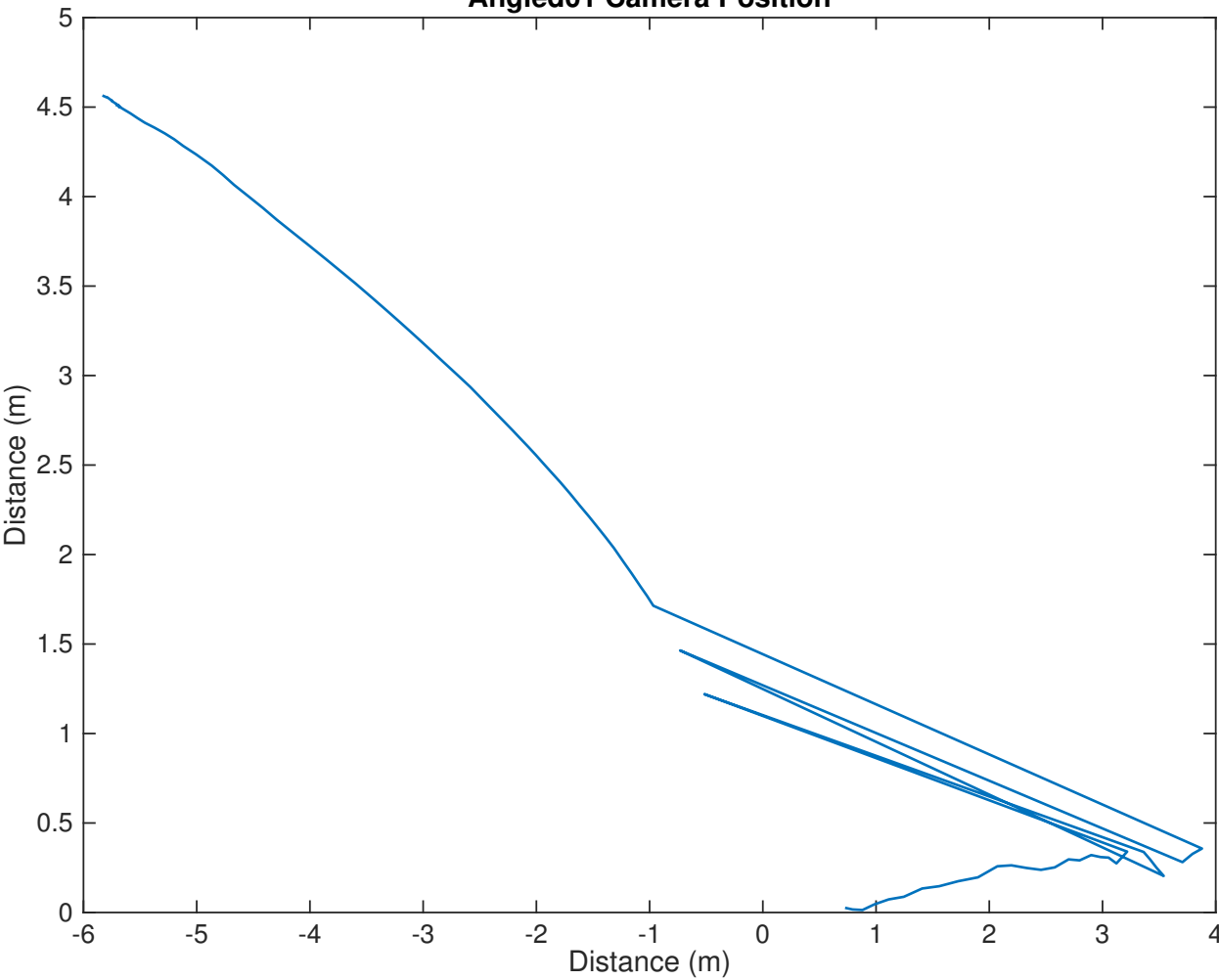
Angled01 Camera vs LIDAR Theta_1



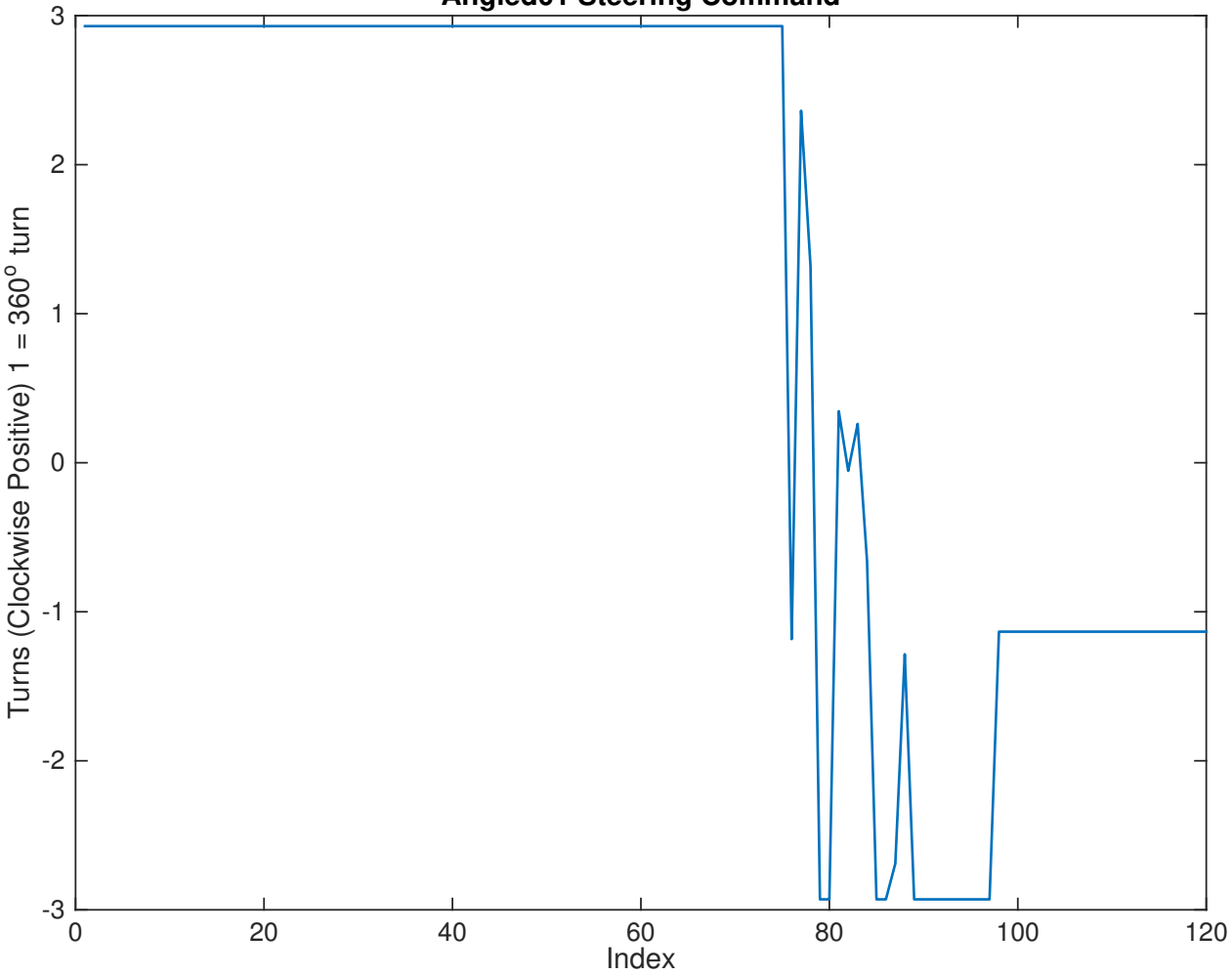
Angled01 Camera vs LIDAR Theta_2



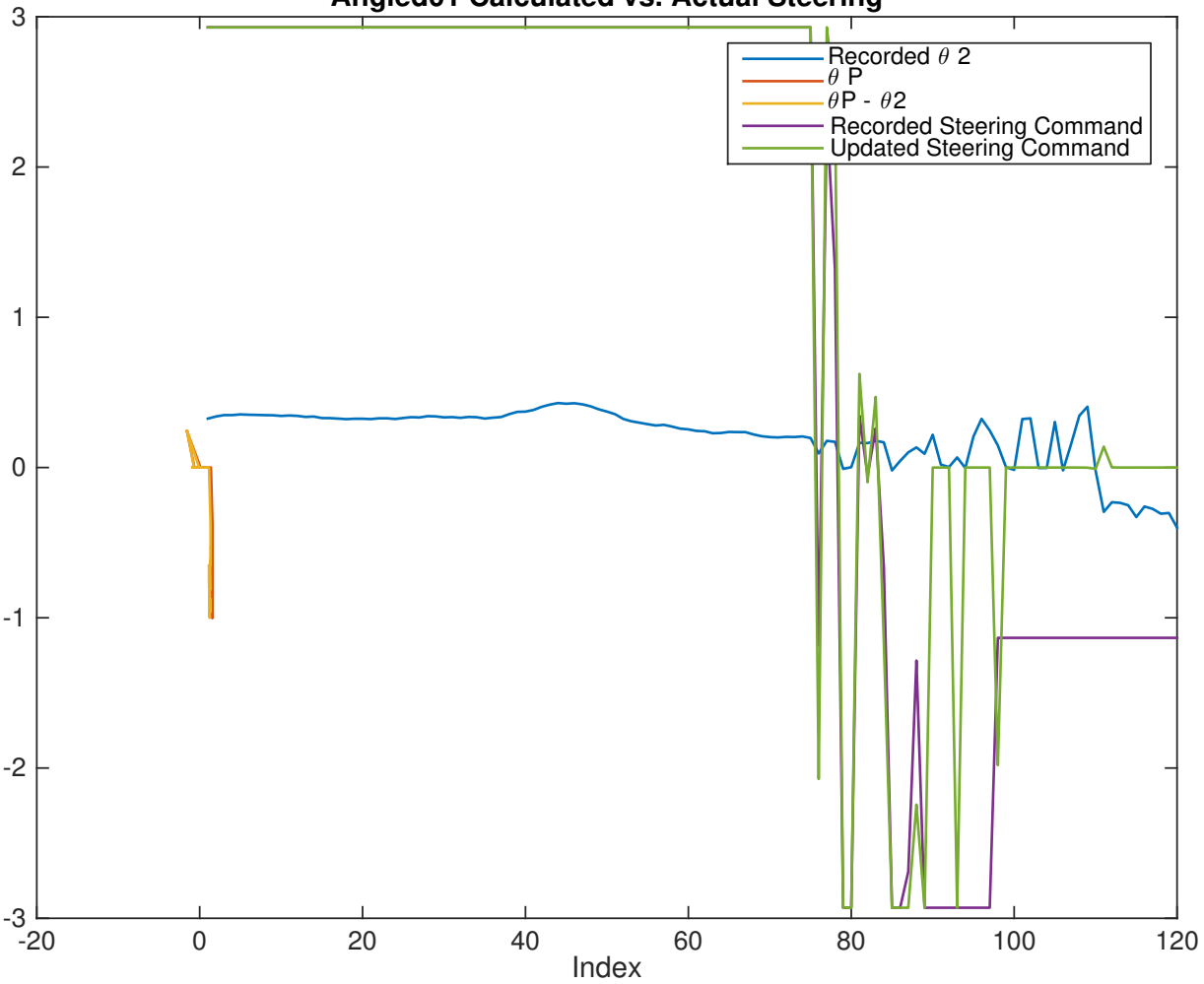
Angled01 Camera Position



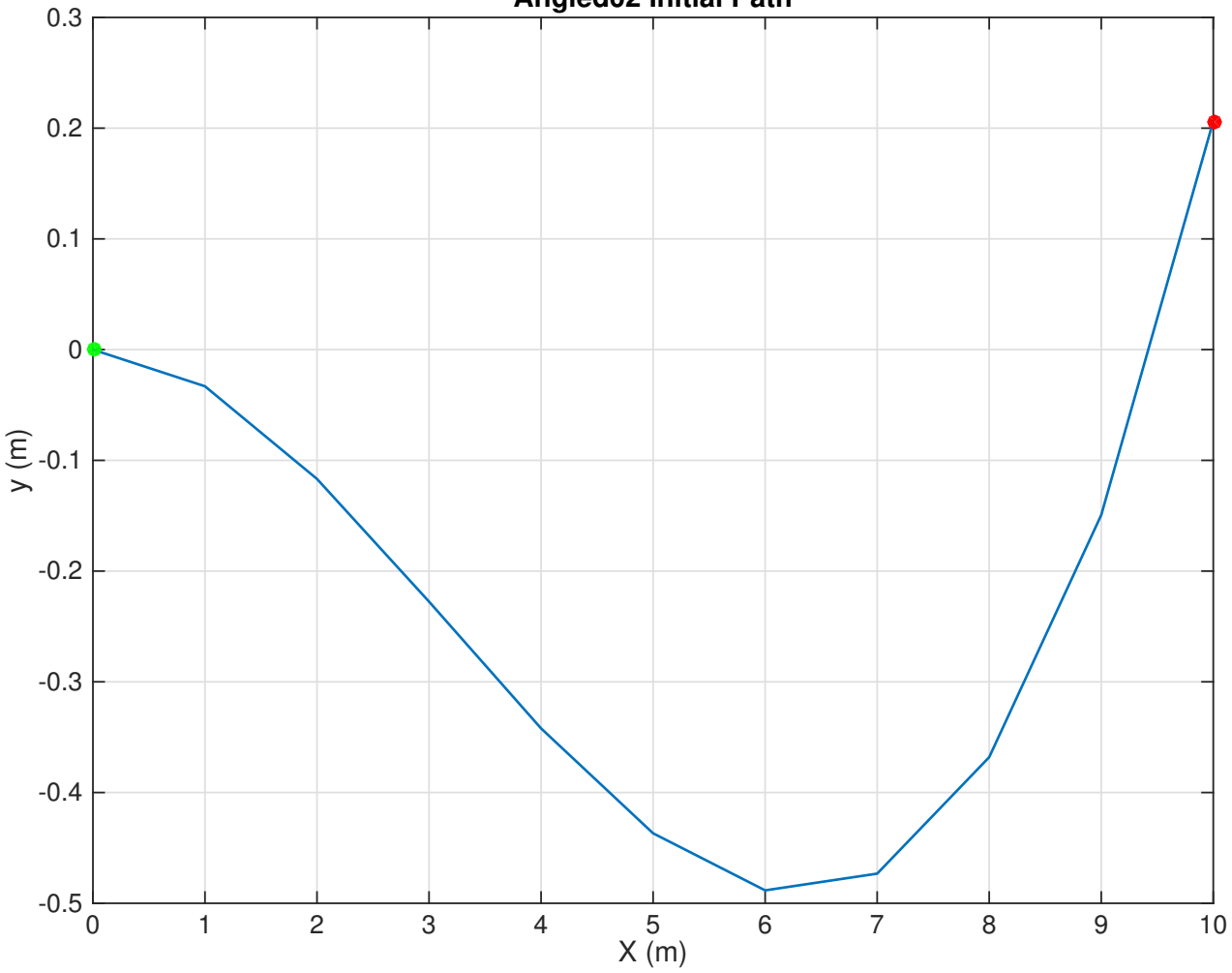
Angled01 Steering Command



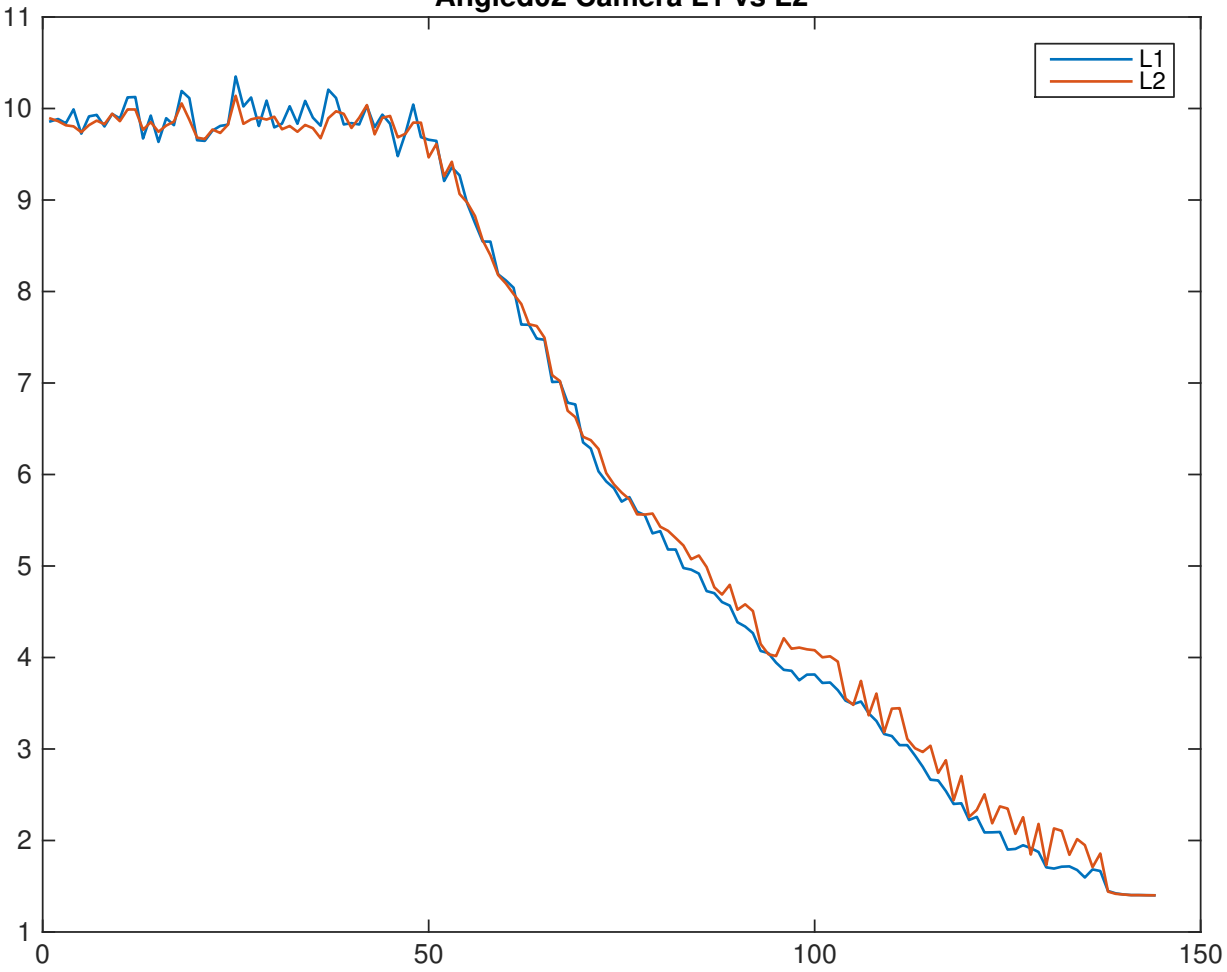
Angled01 Calculated vs. Actual Steering



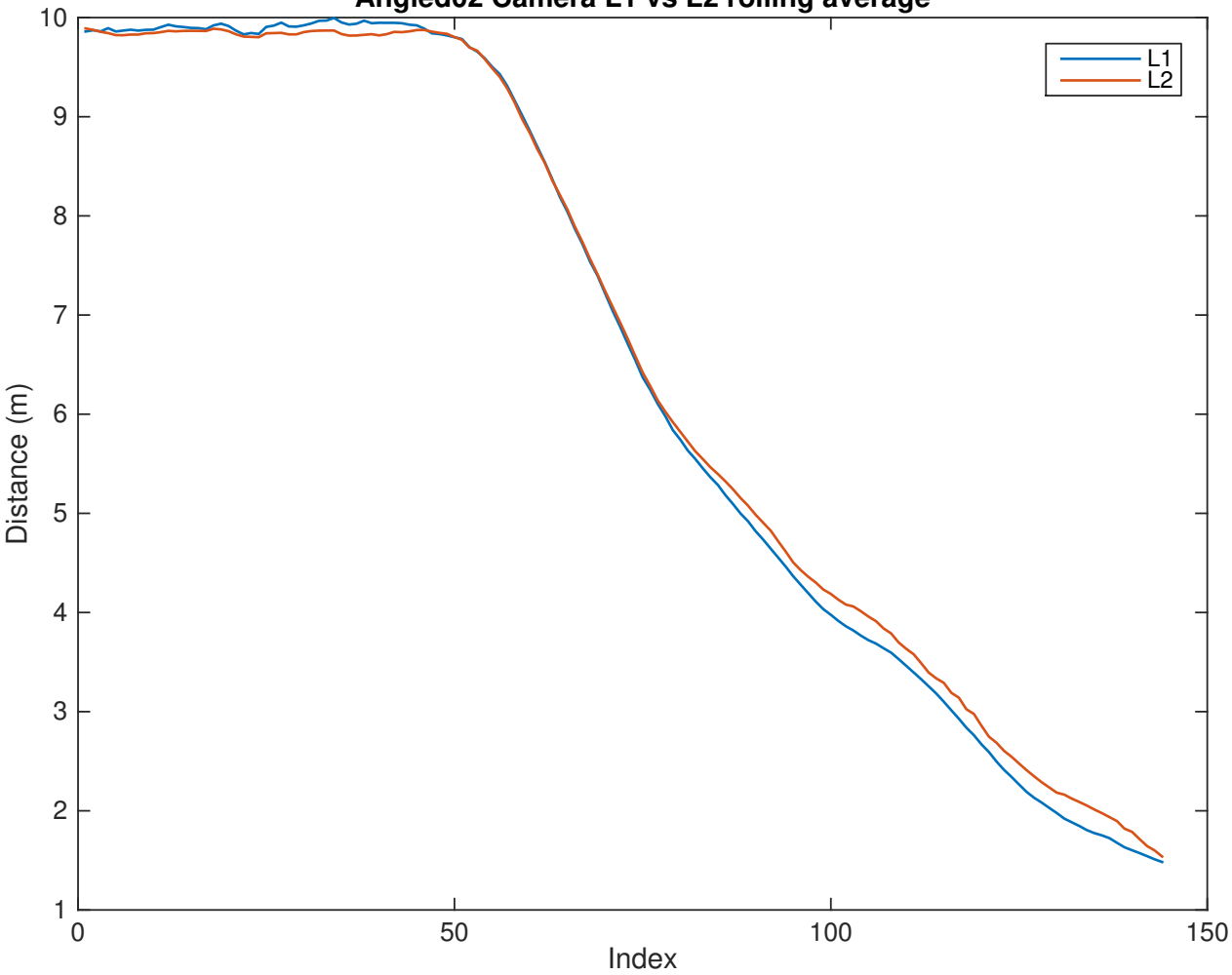
Angled02 Initial Path



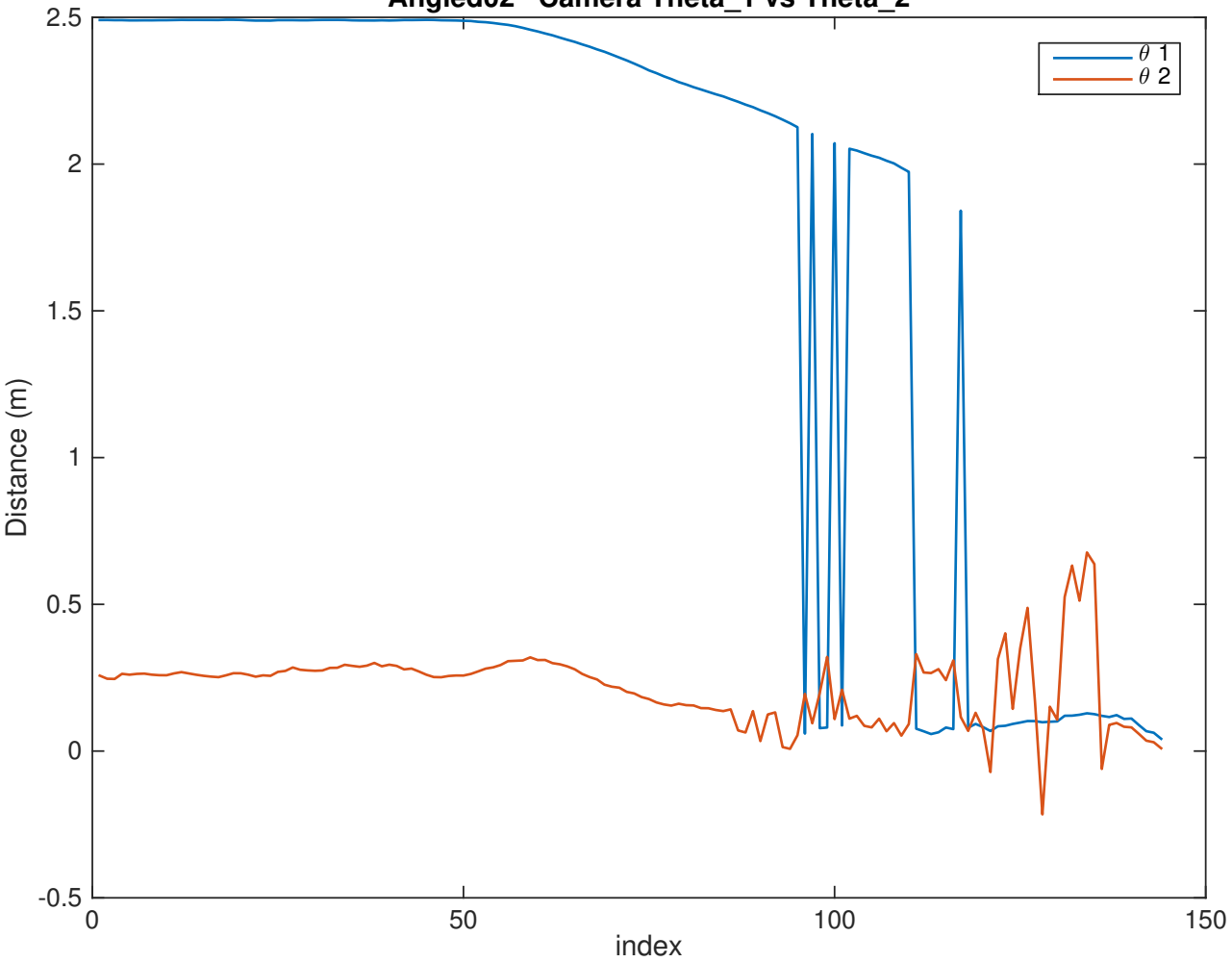
Angled02 Camera L1 vs L2



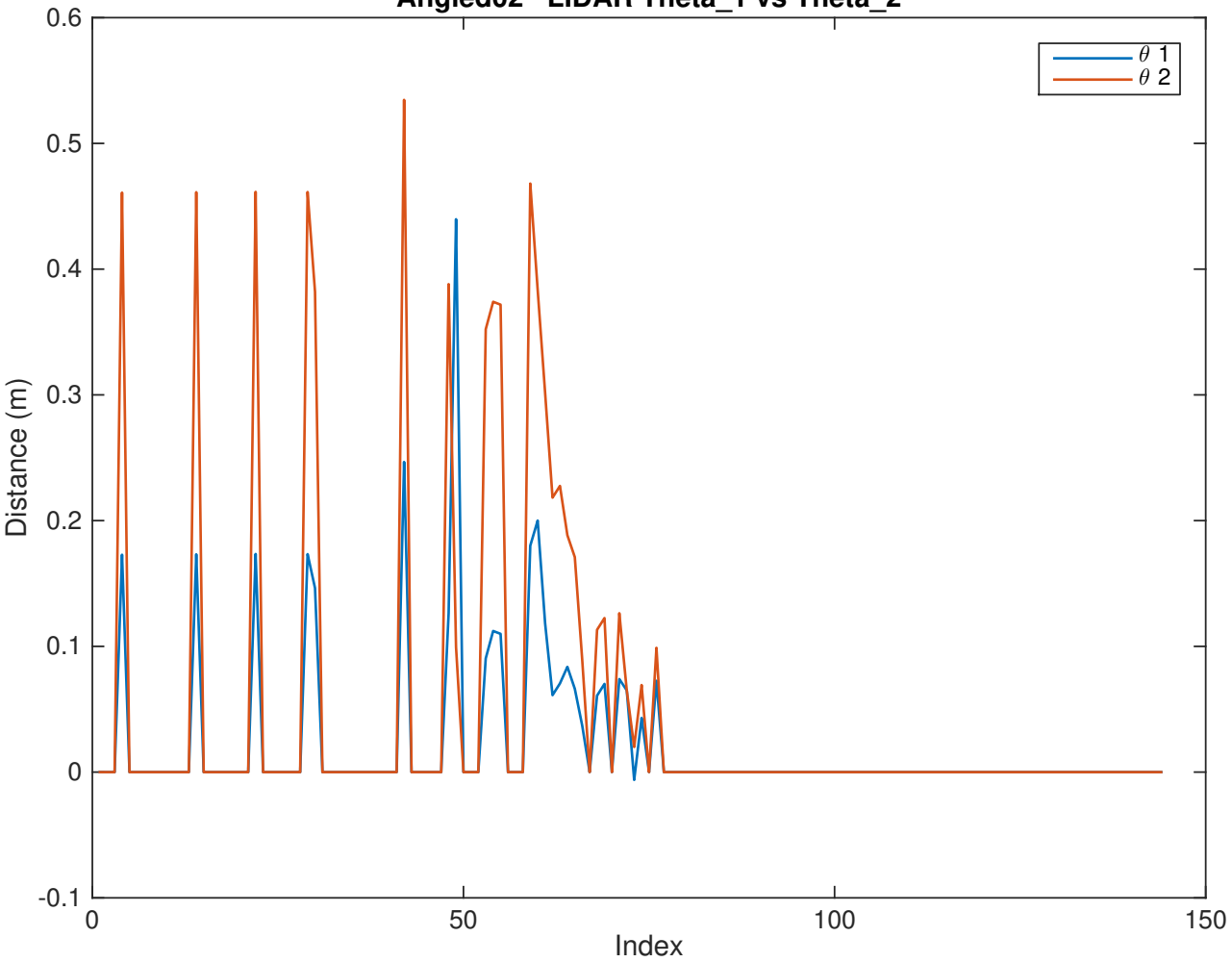
Angled02 Camera L1 vs L2 rolling average



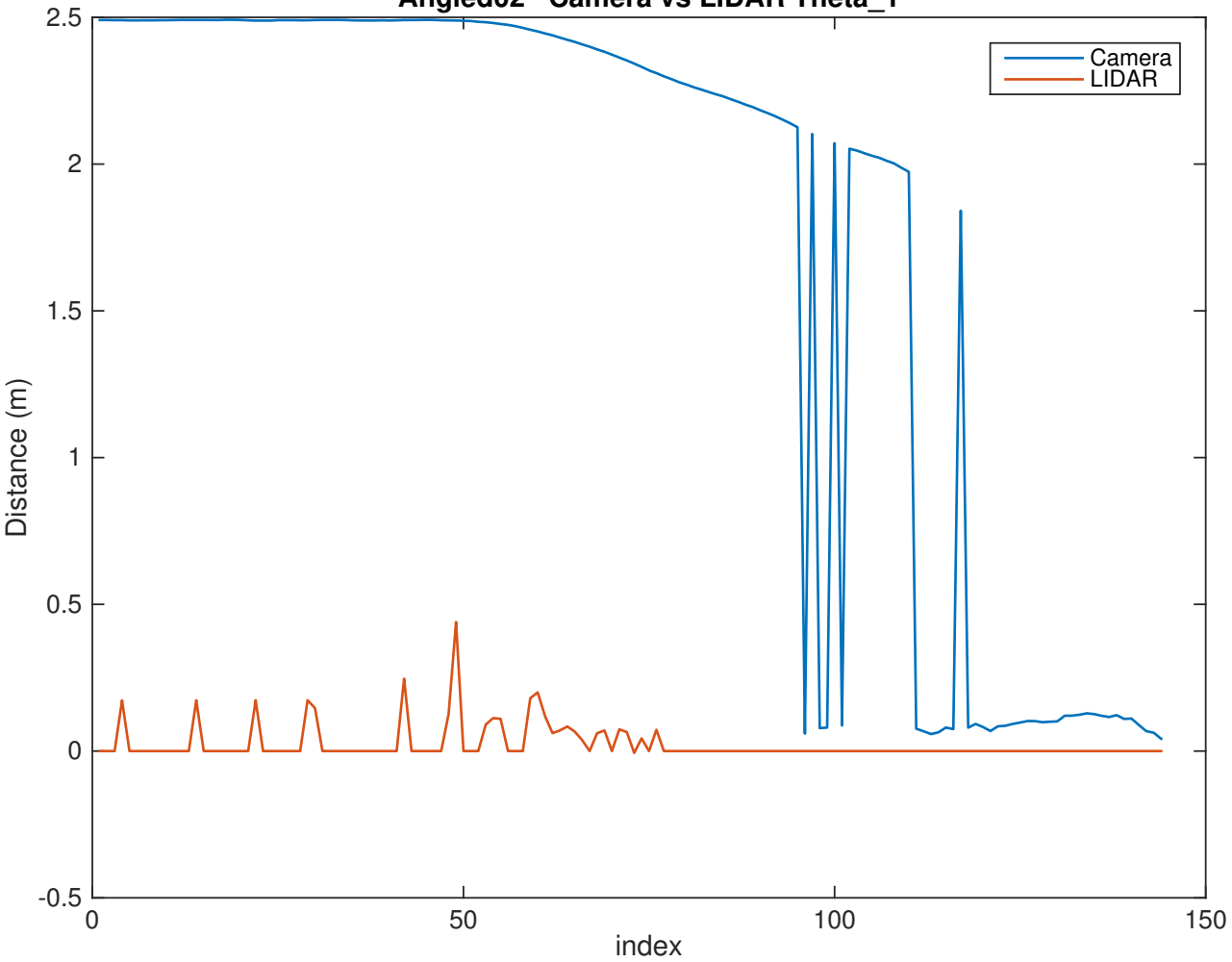
Angled02 Camera Theta_1 vs Theta_2



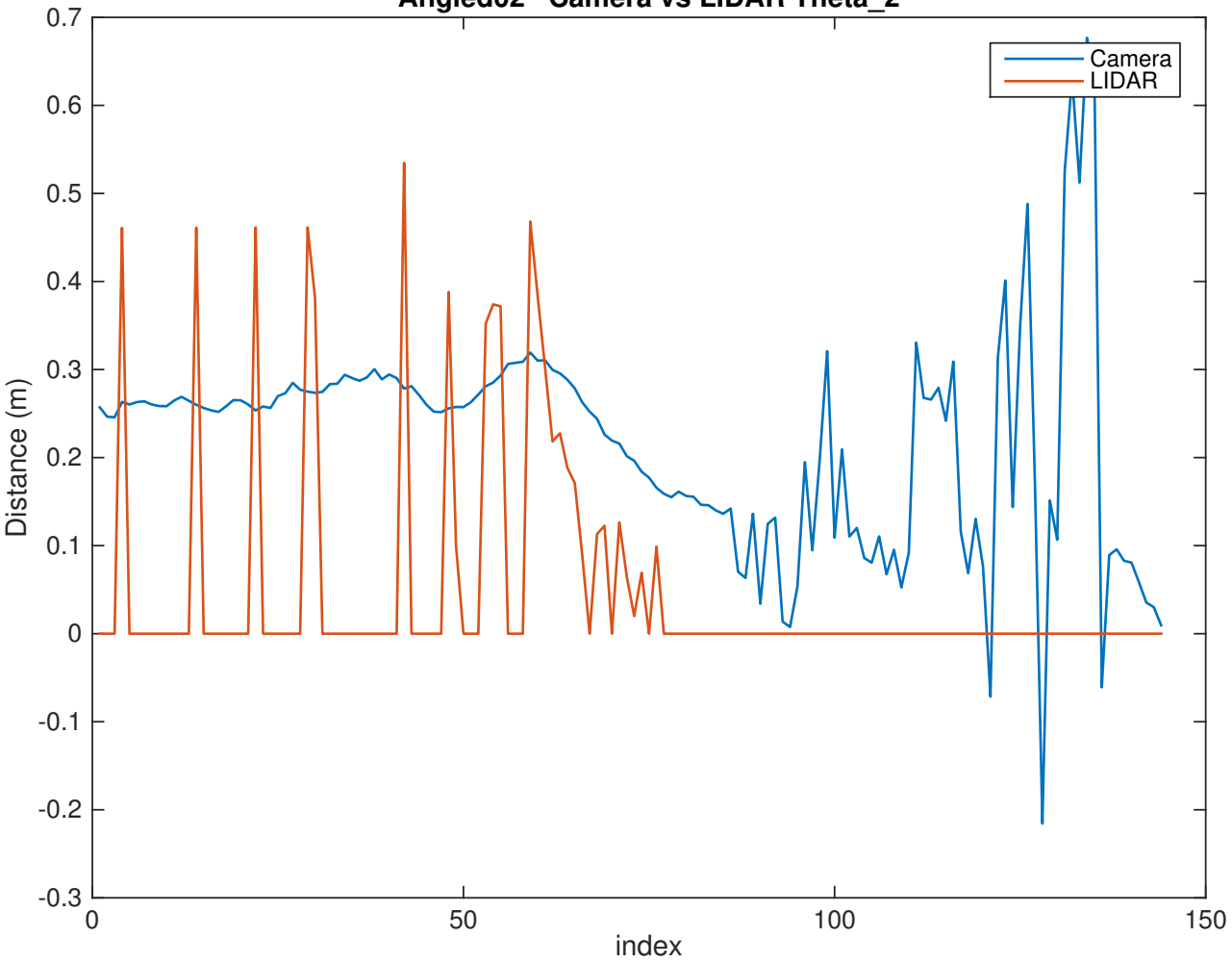
Angled02 LIDAR Theta_1 vs Theta_2



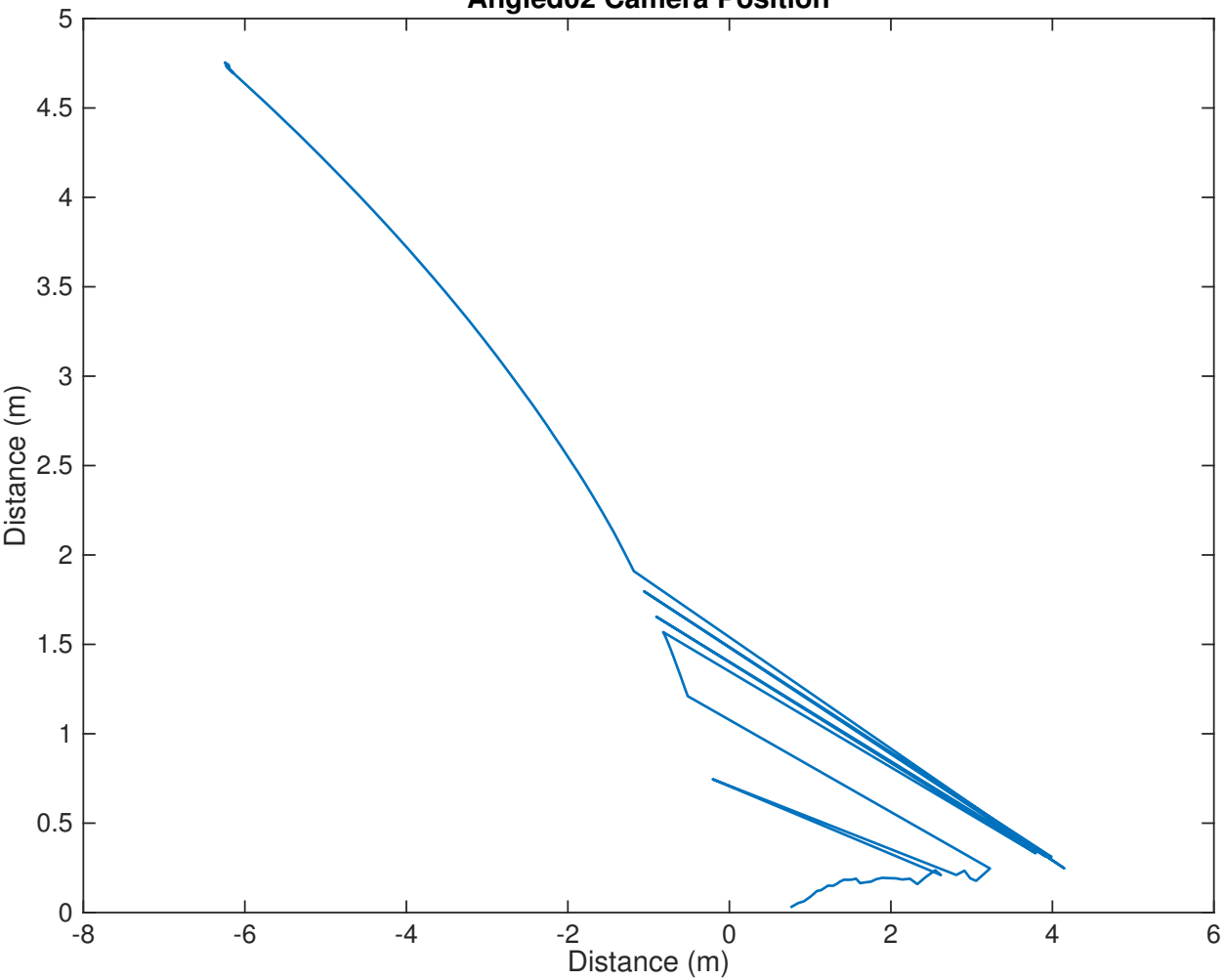
Angled02 Camera vs LIDAR Theta_1



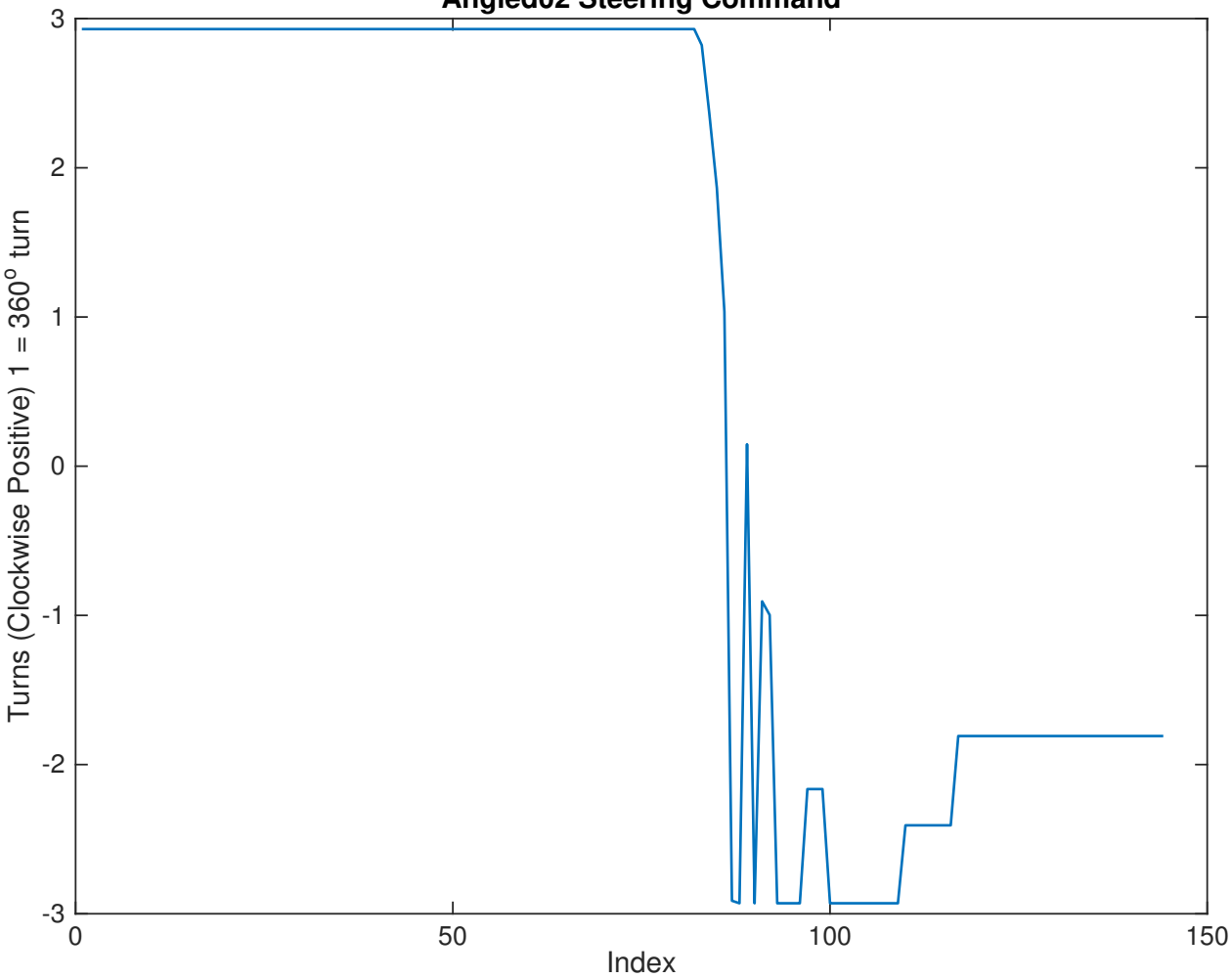
Angled02 Camera vs LIDAR Theta_2



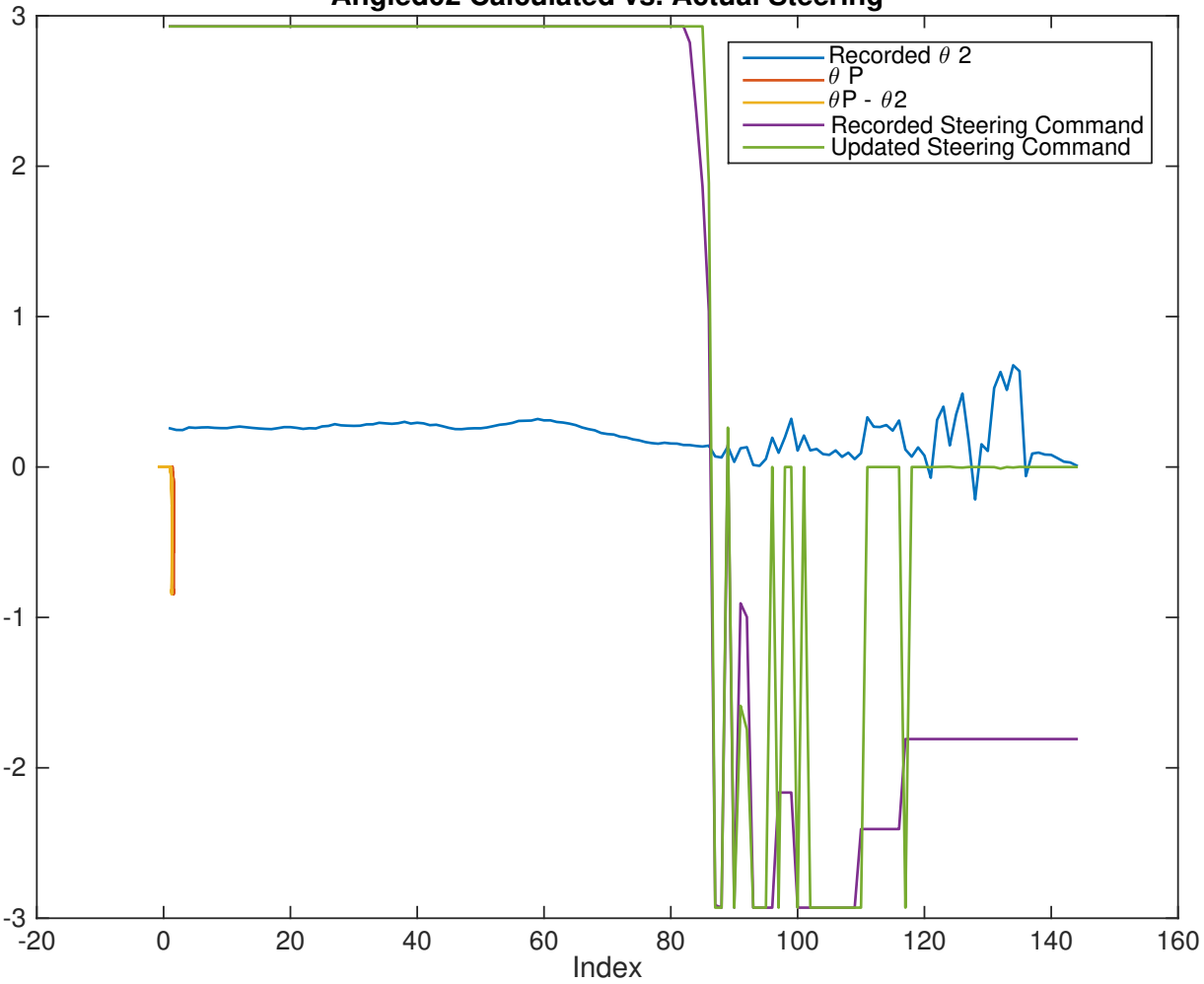
Angled02 Camera Position



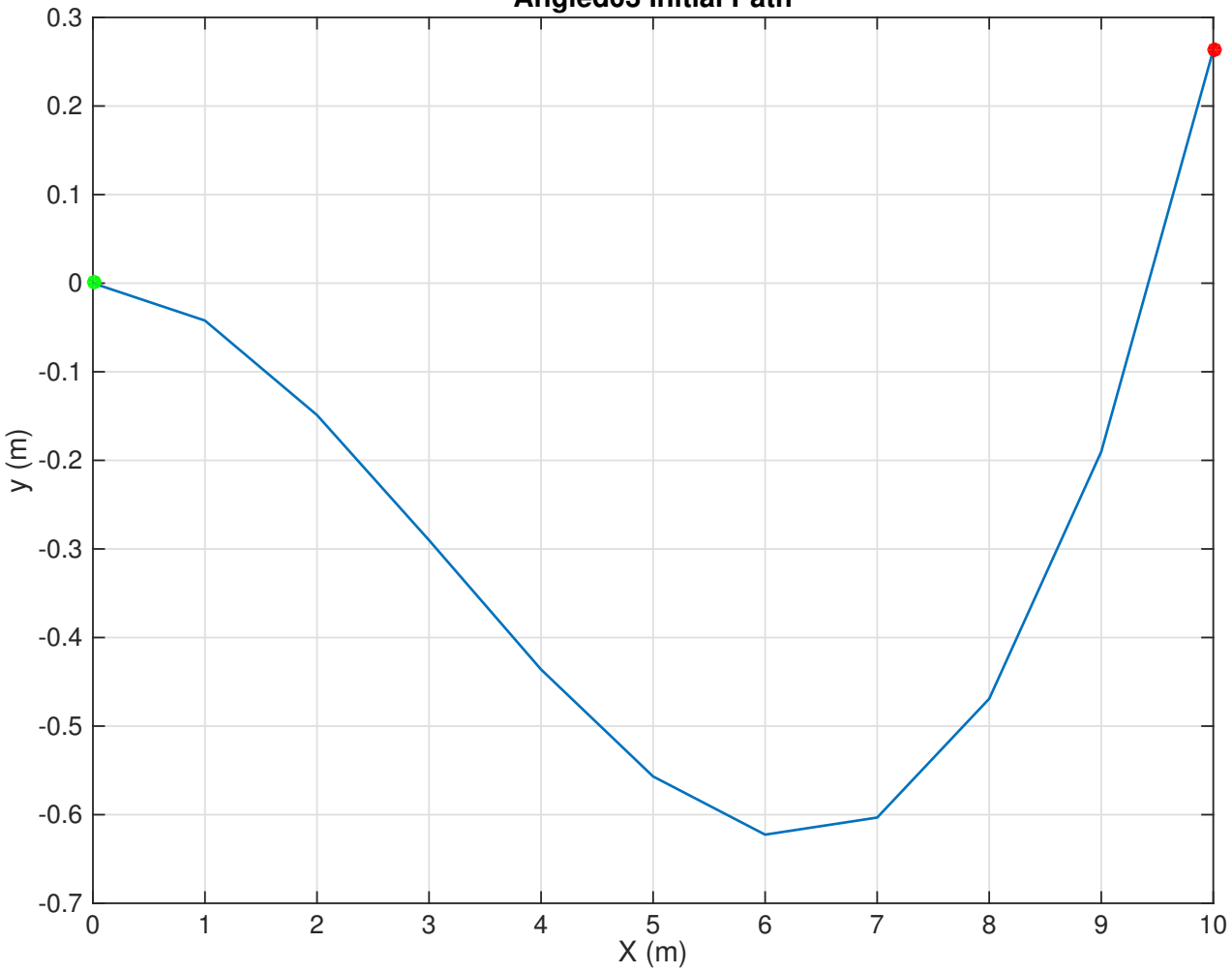
Angled02 Steering Command



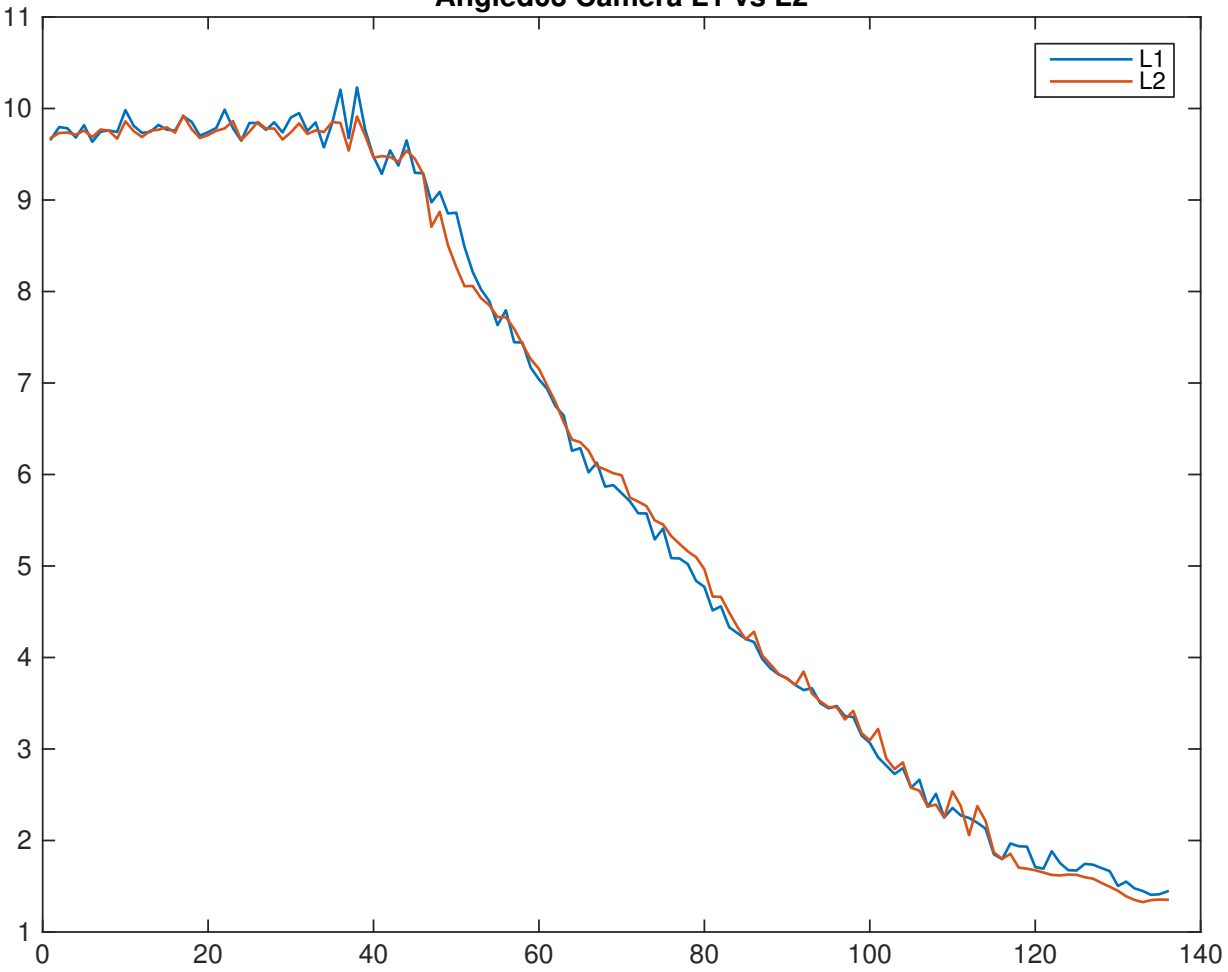
Angled02 Calculated vs. Actual Steering



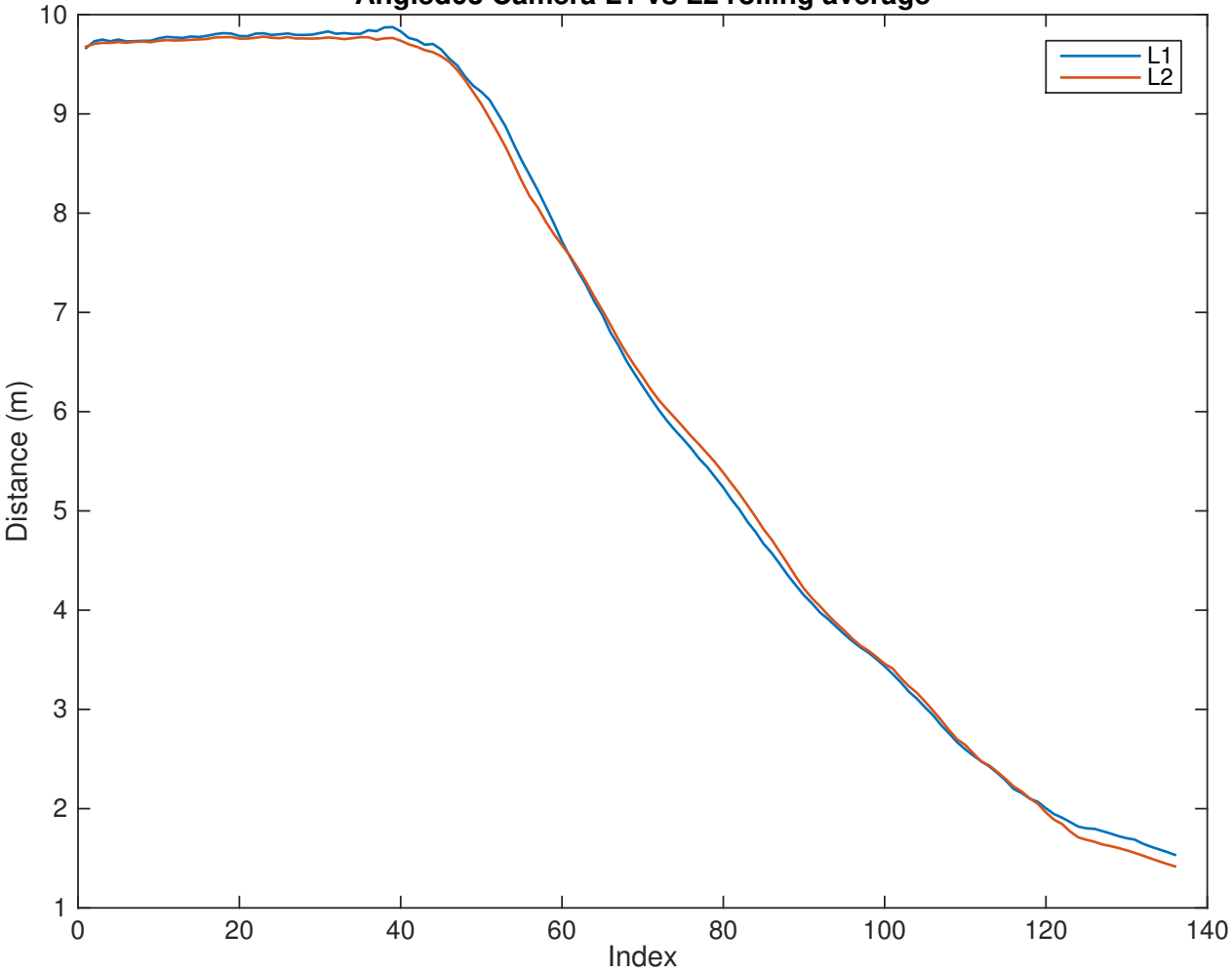
Angled03 Initial Path



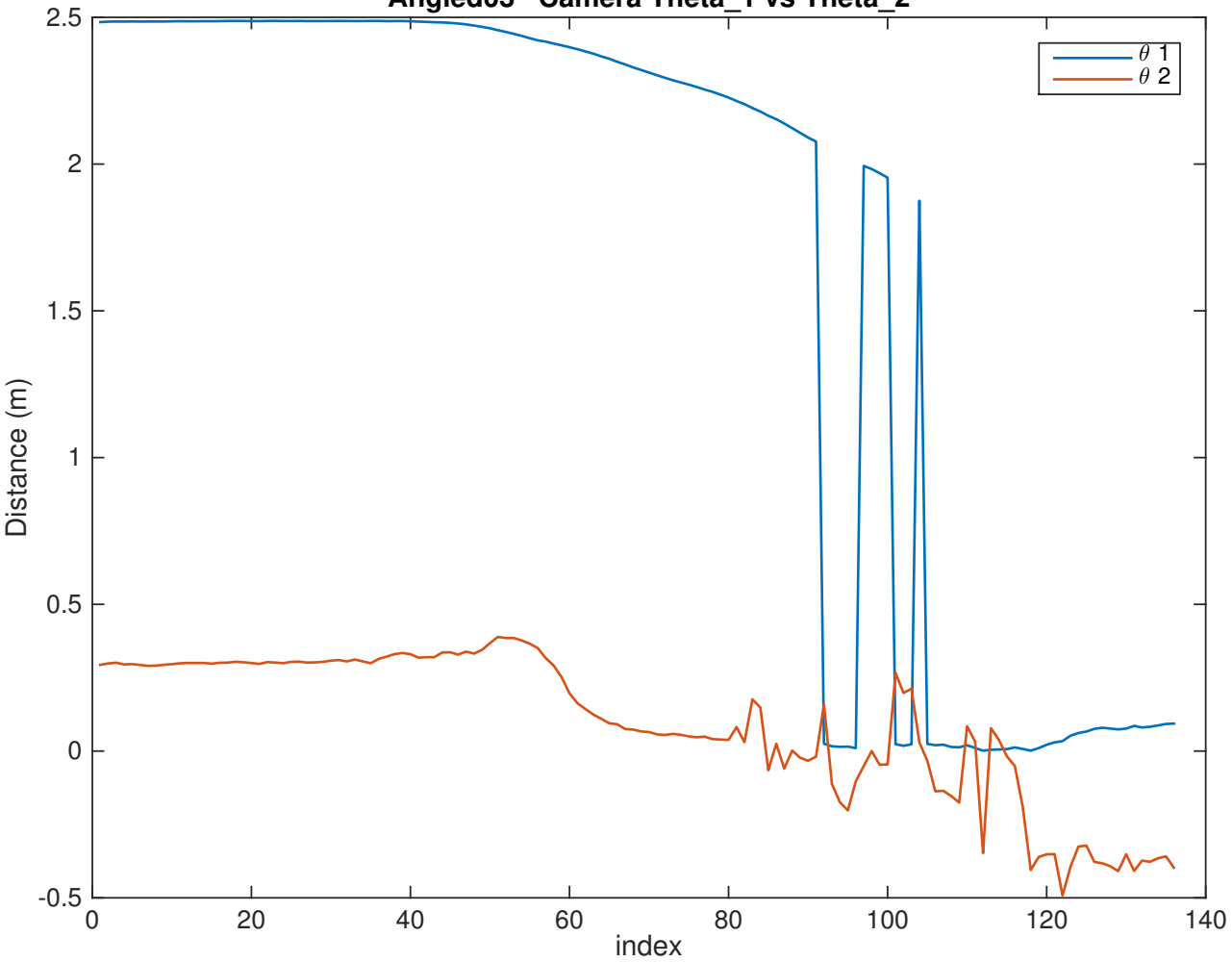
Angled03 Camera L1 vs L2



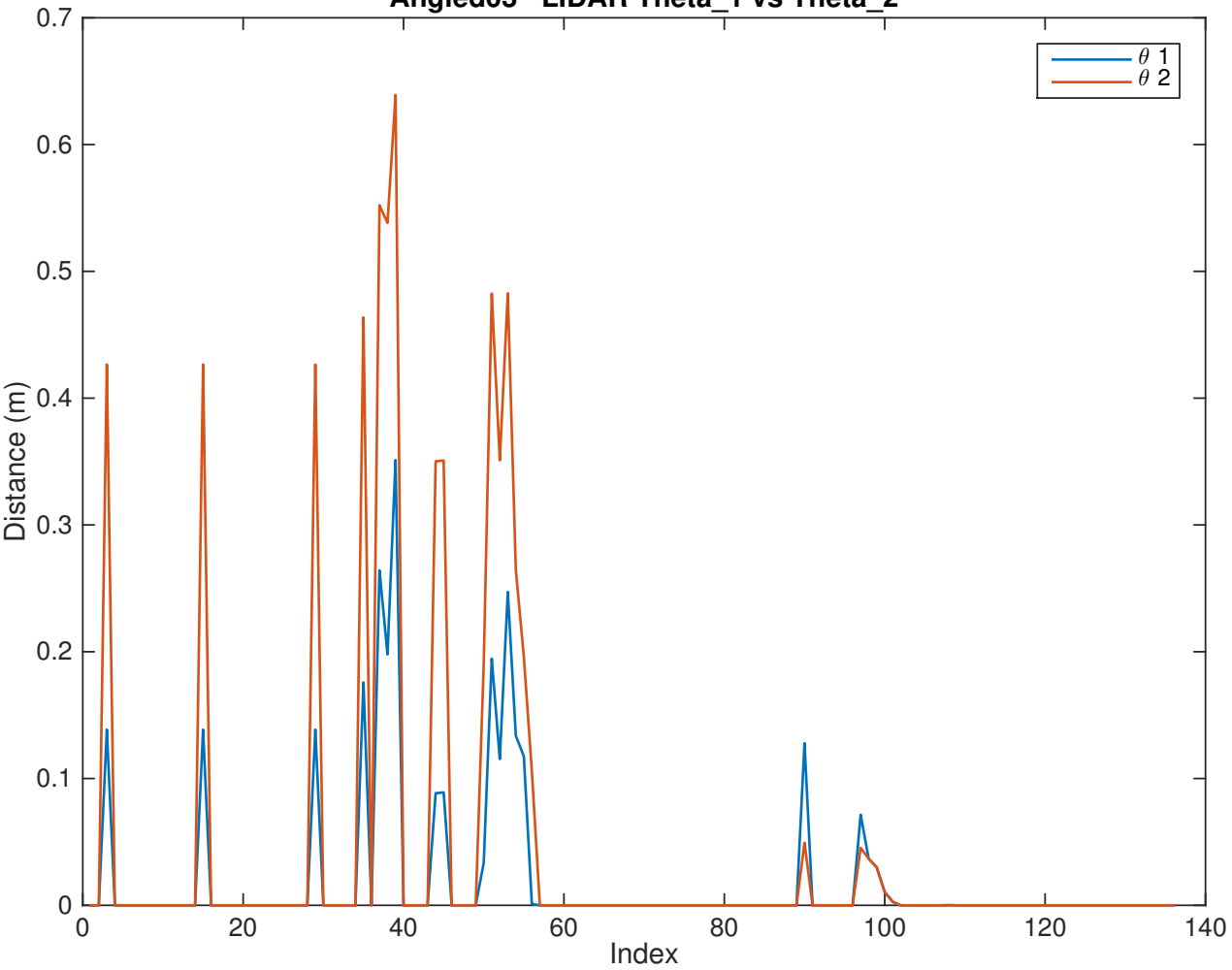
Angled03 Camera L1 vs L2 rolling average



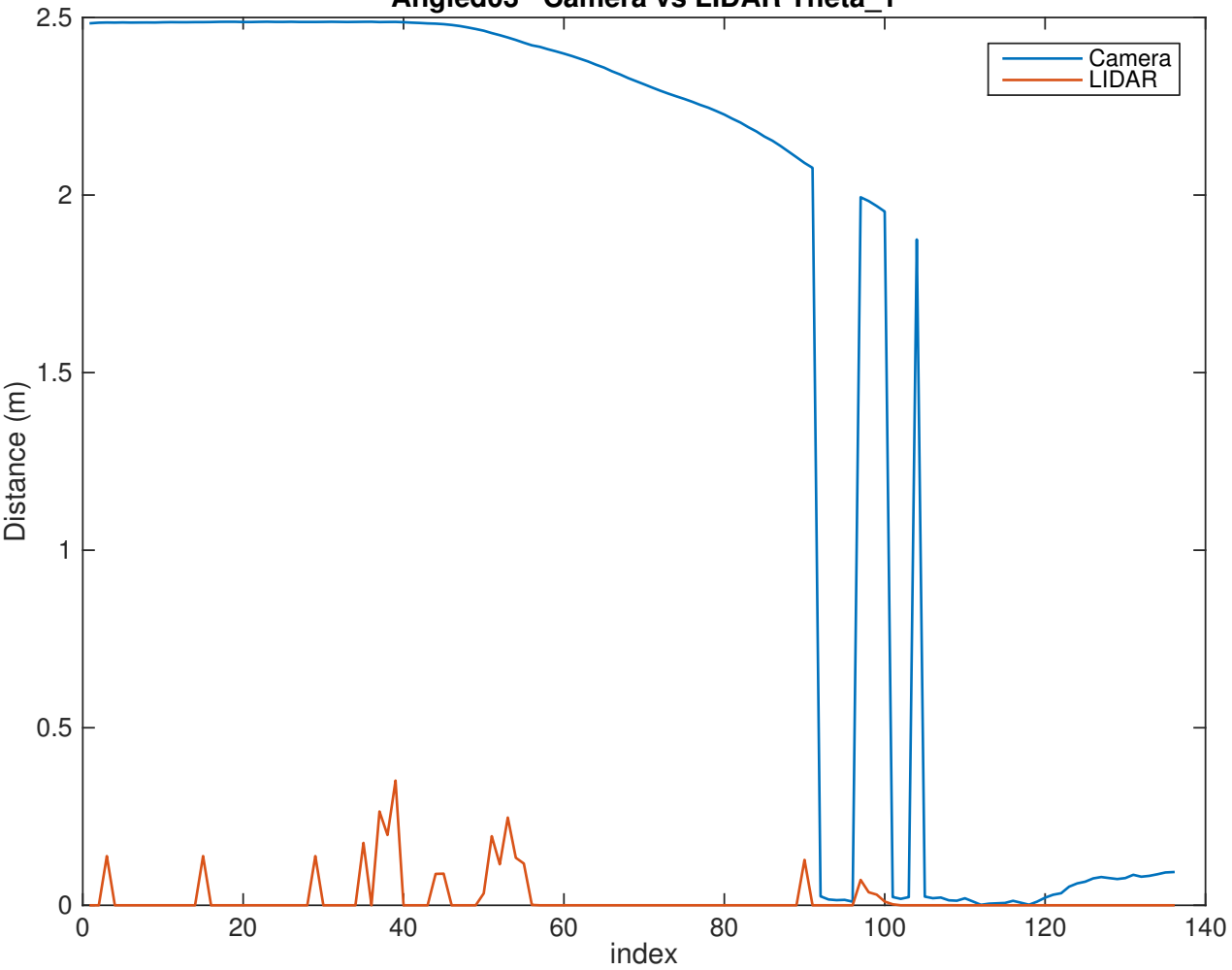
Angled03 Camera Theta_1 vs Theta_2



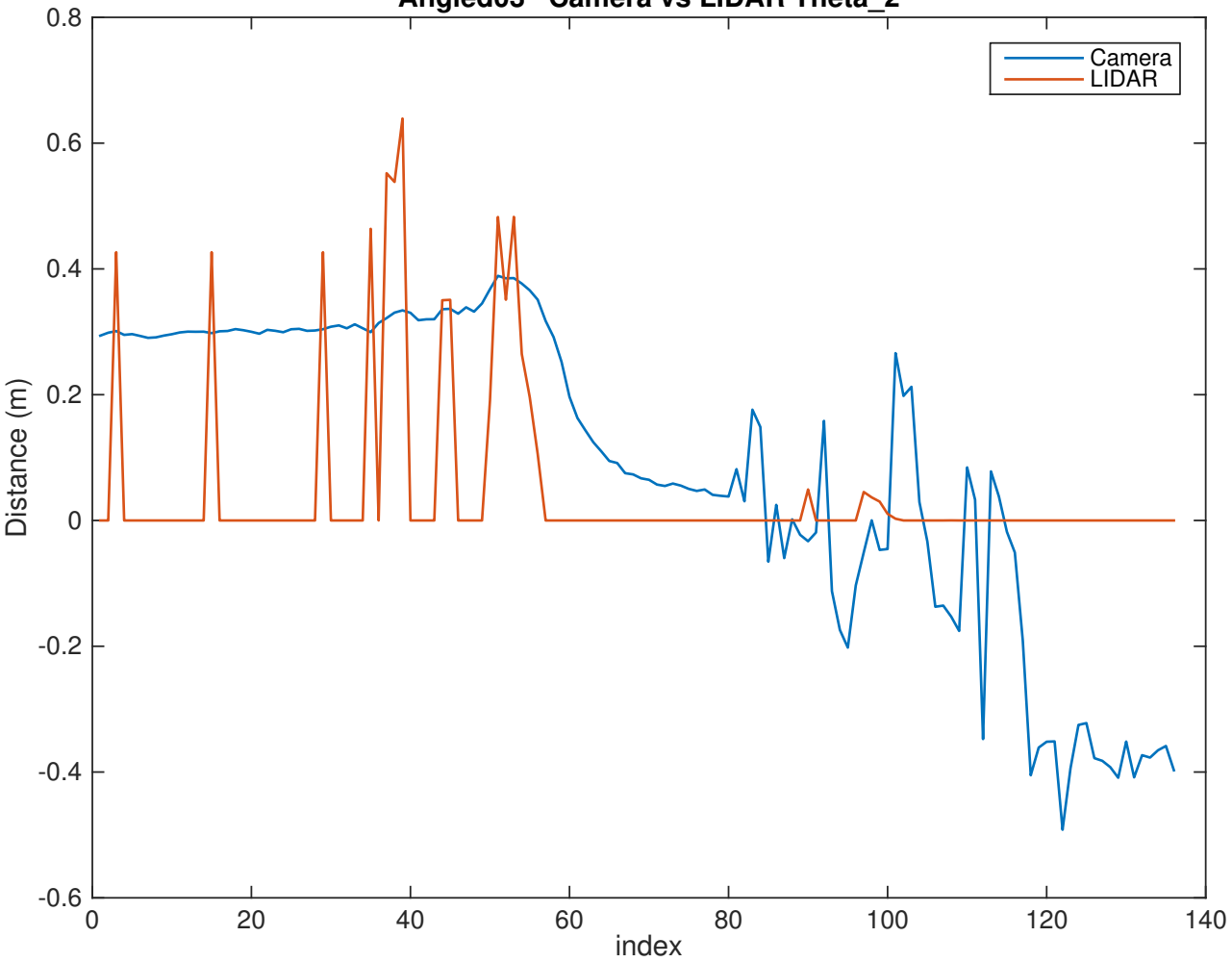
Angled03 LIDAR Theta_1 vs Theta_2



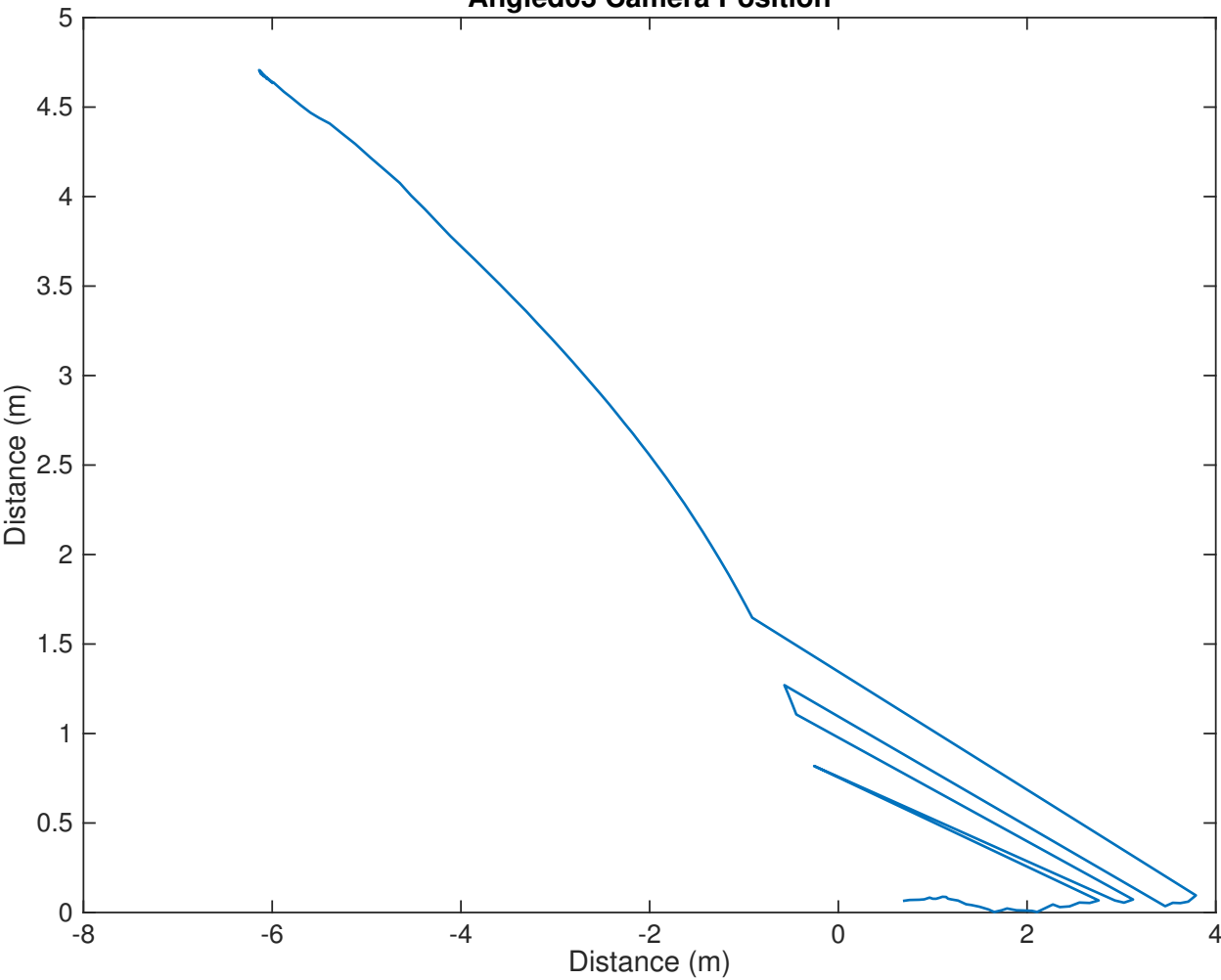
Angled03 Camera vs LIDAR Theta_1



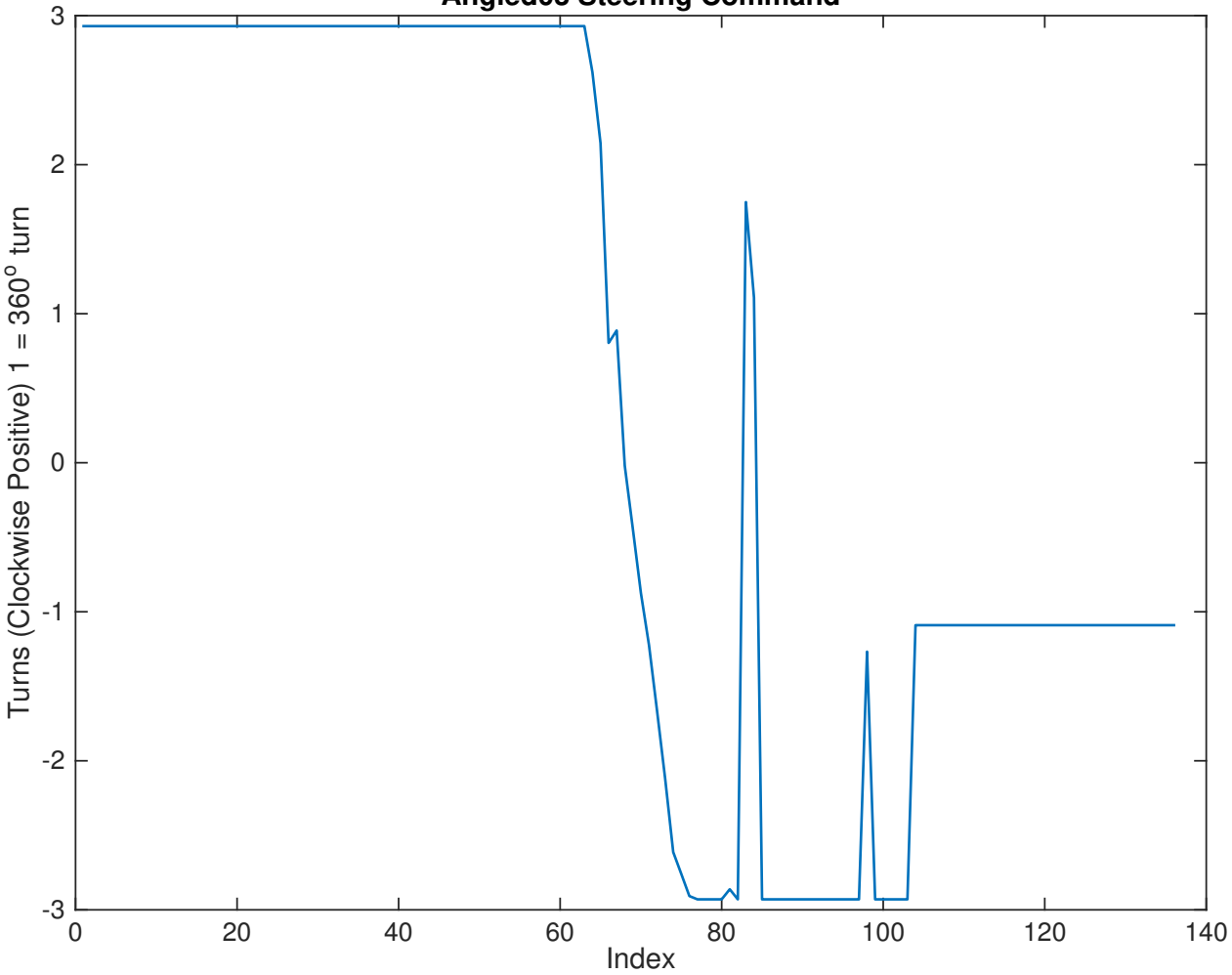
Angled03 Camera vs LIDAR Theta_2



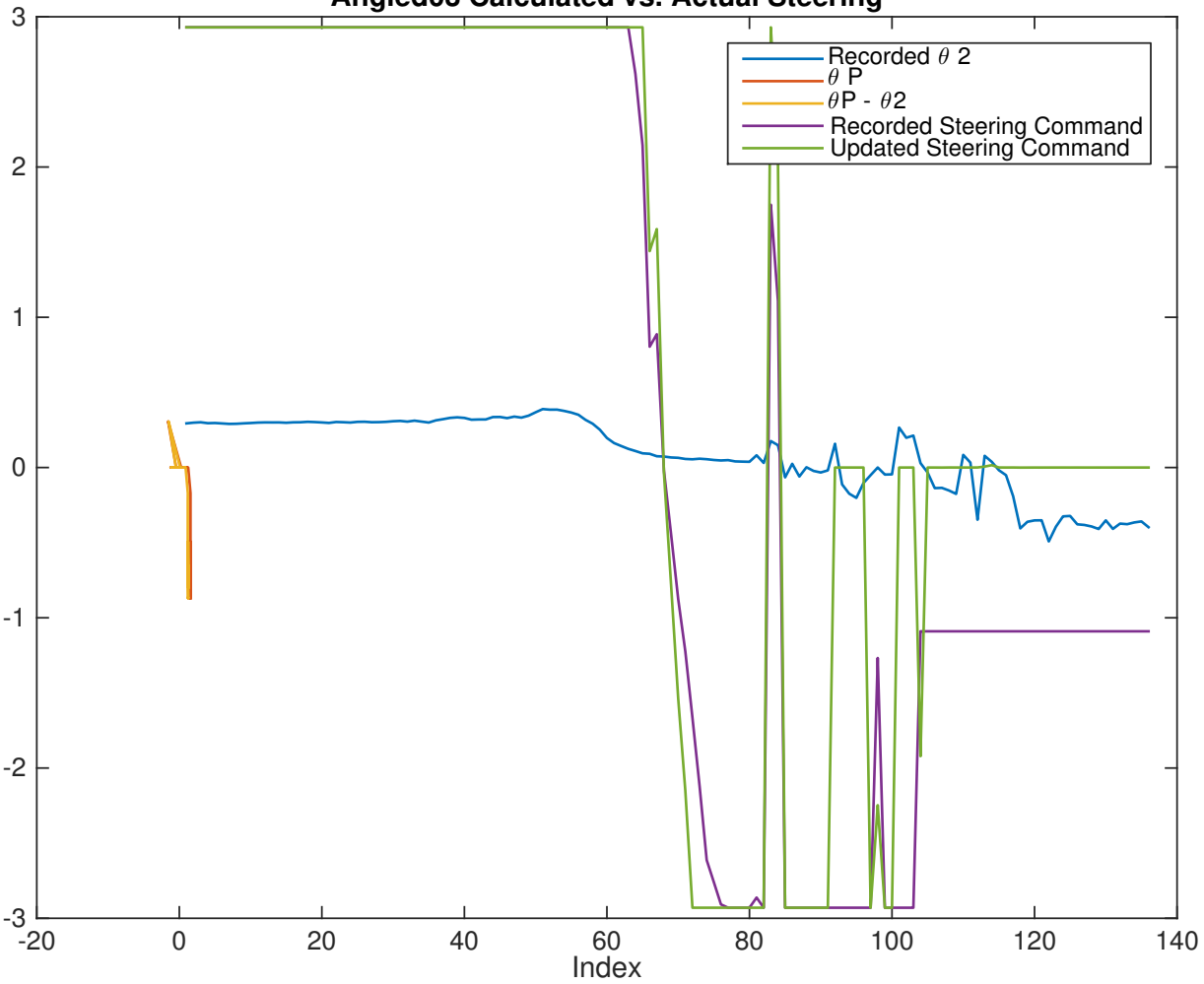
Angled03 Camera Position



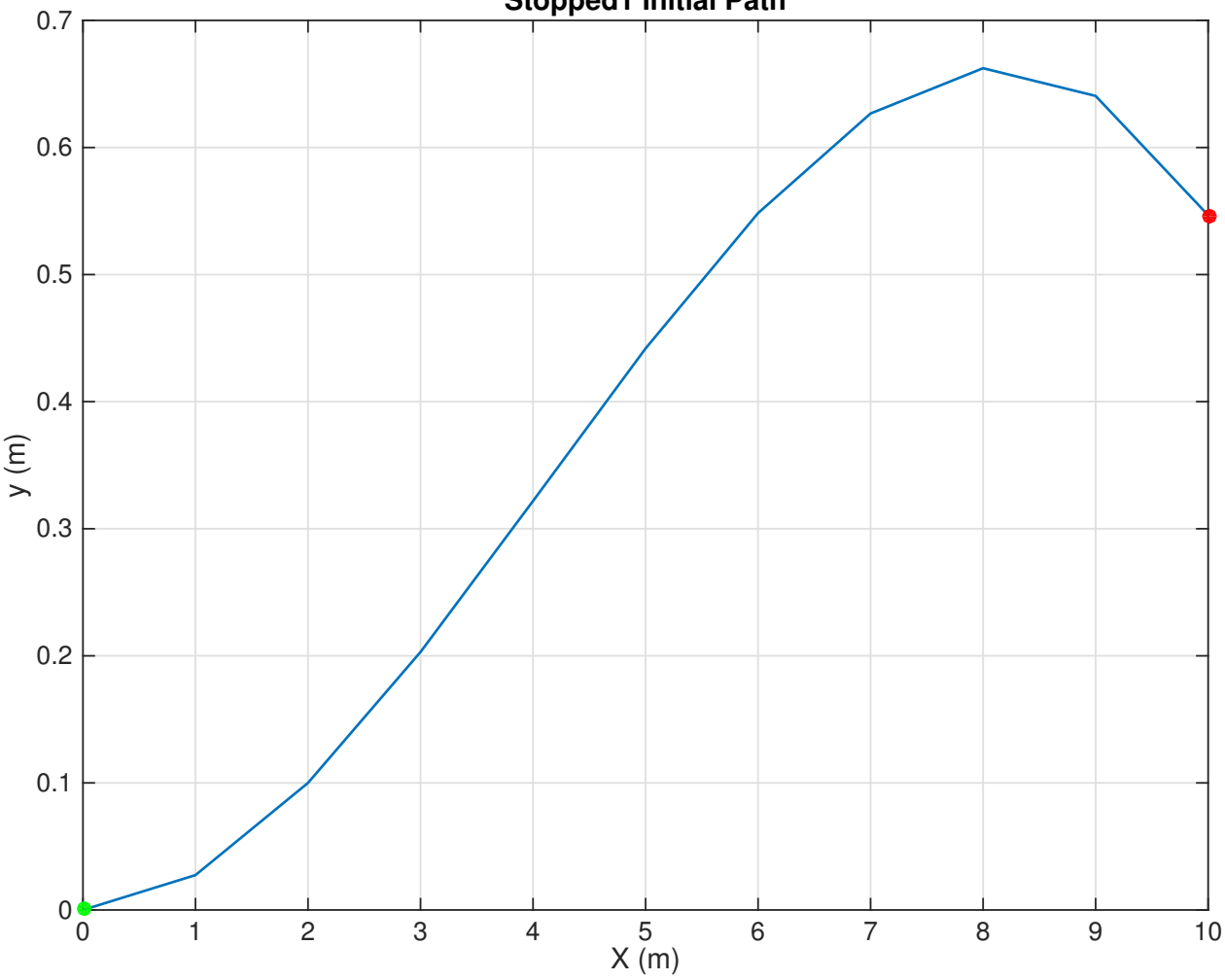
Angled03 Steering Command



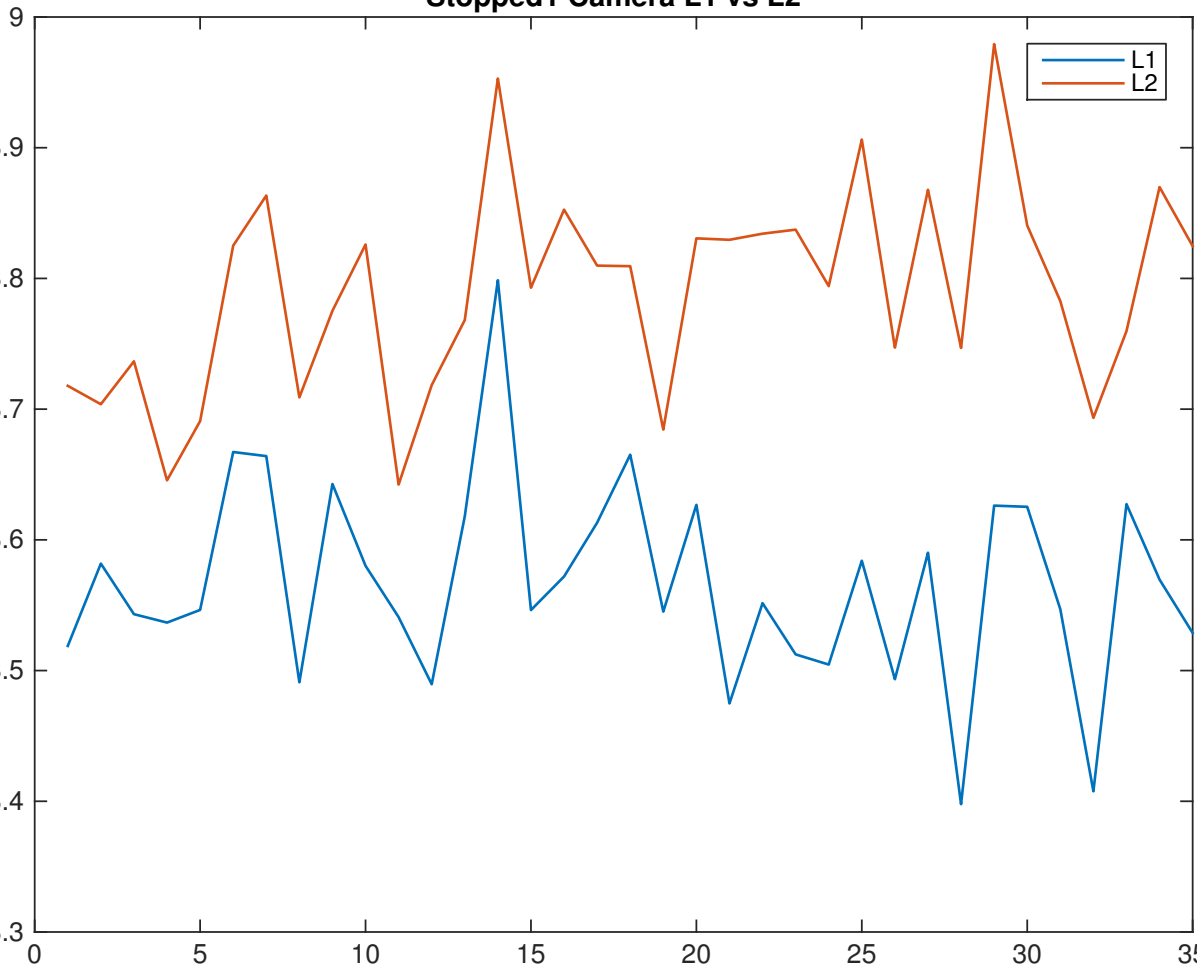
Angled03 Calculated vs. Actual Steering



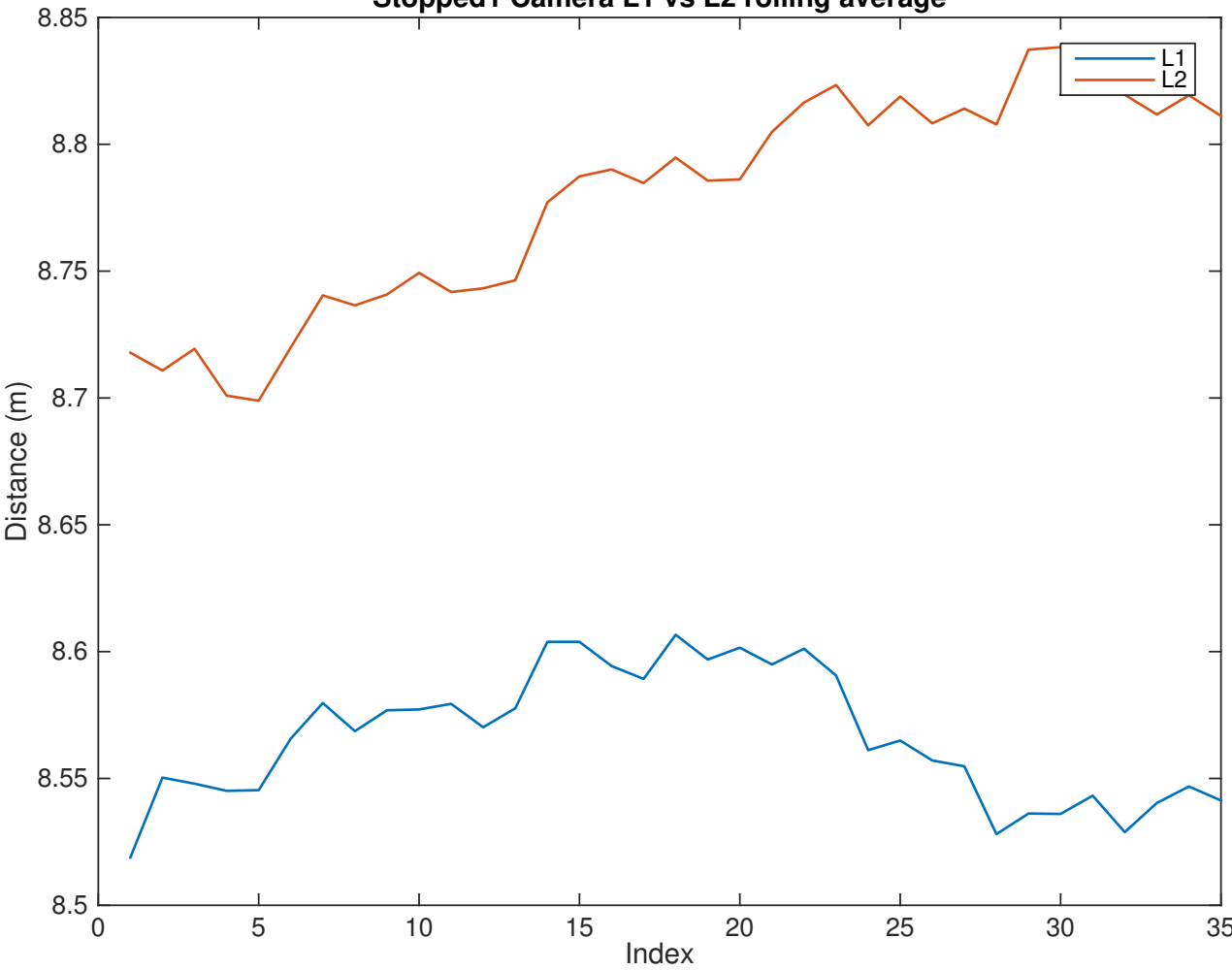
Stopped1 Initial Path



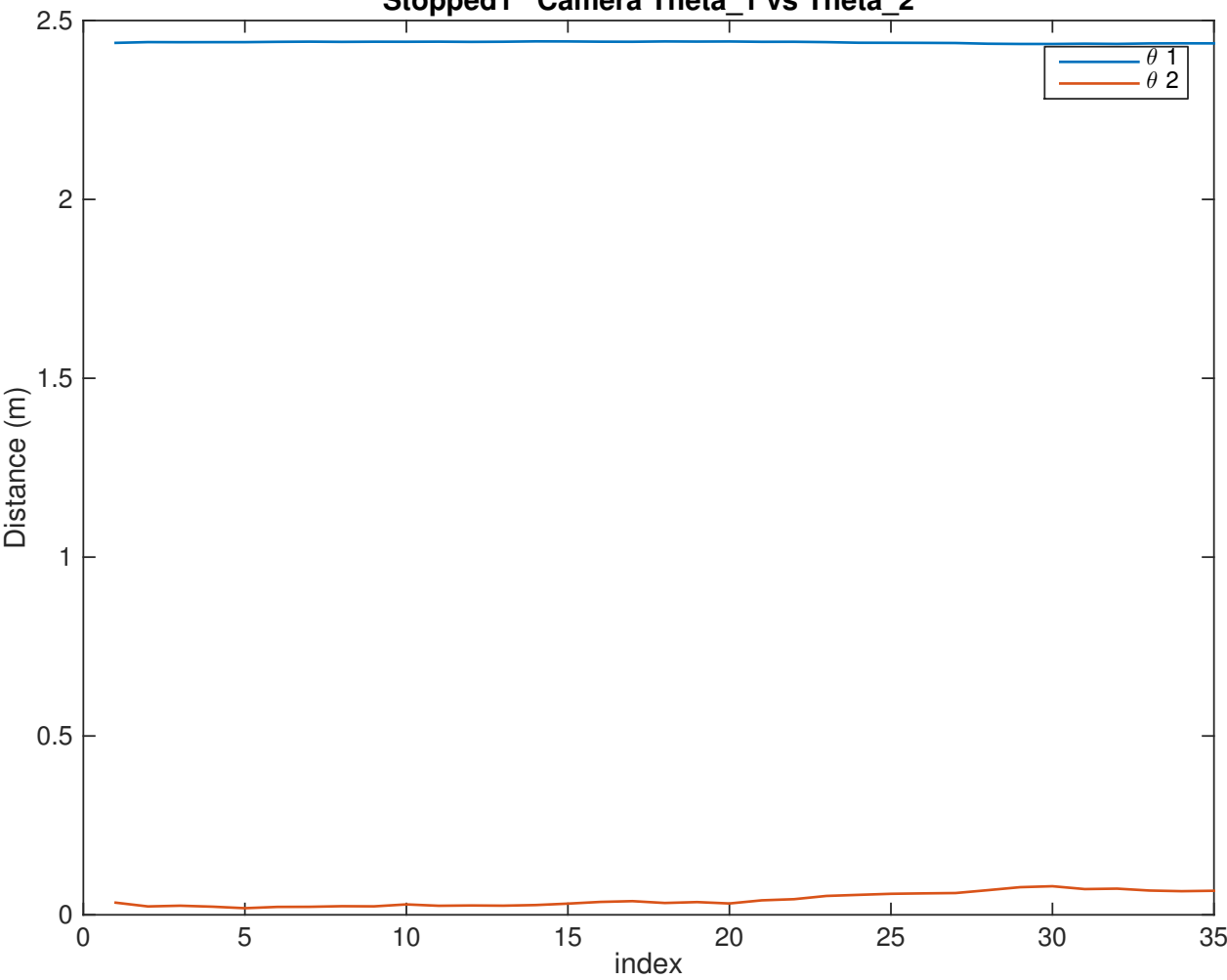
Stopped1 Camera L1 vs L2



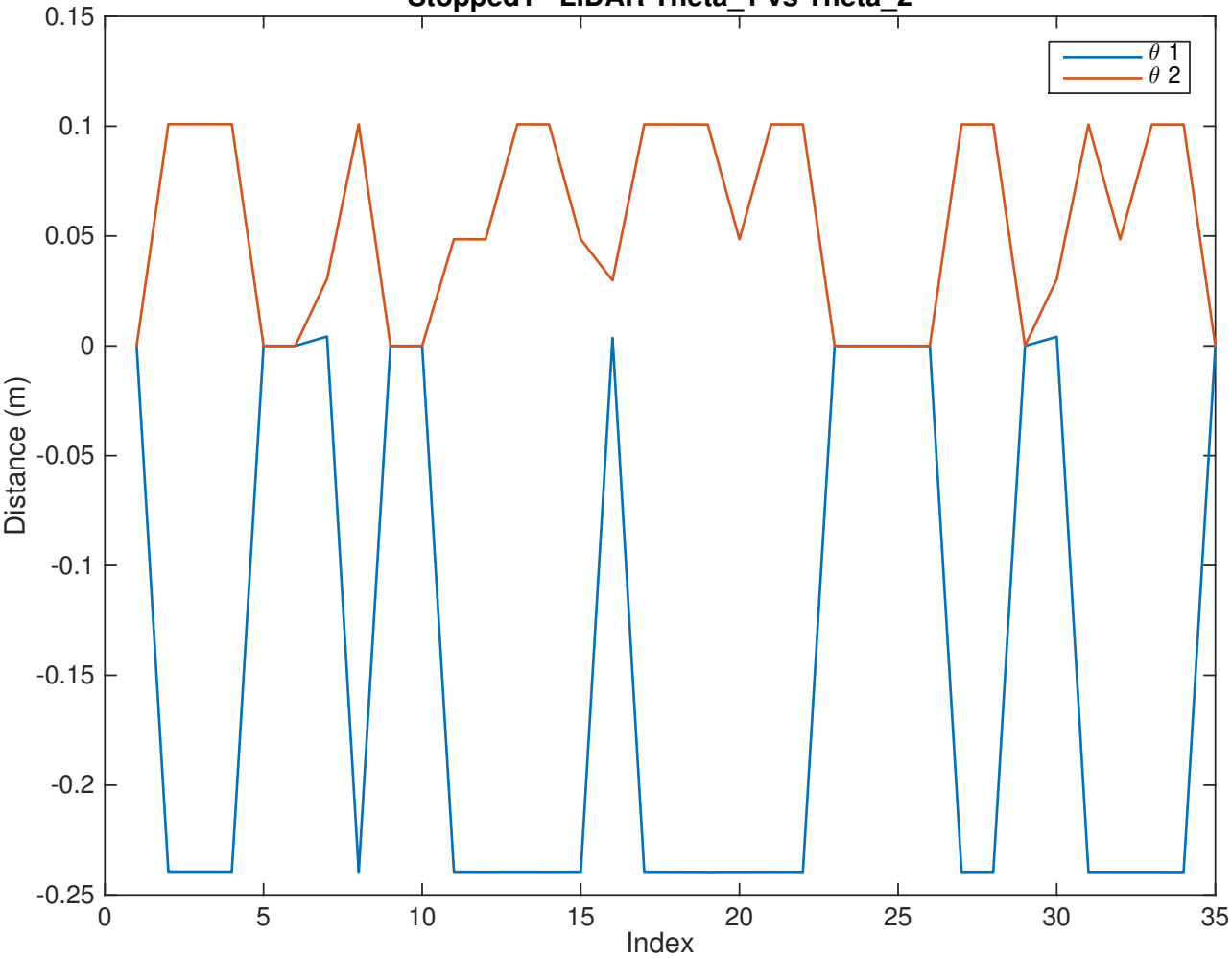
Stopped1 Camera L1 vs L2 rolling average



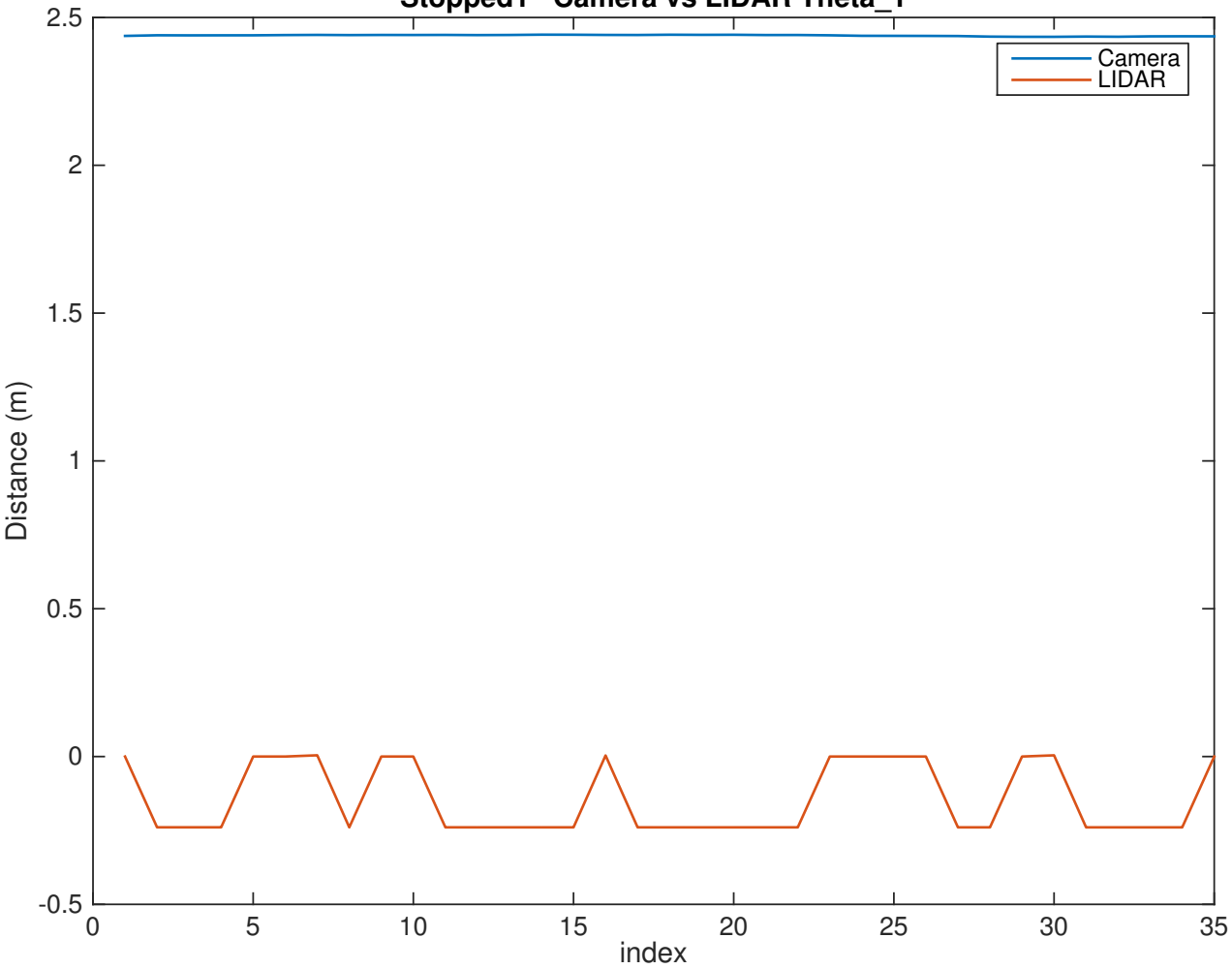
Stopped1 Camera Theta_1 vs Theta_2



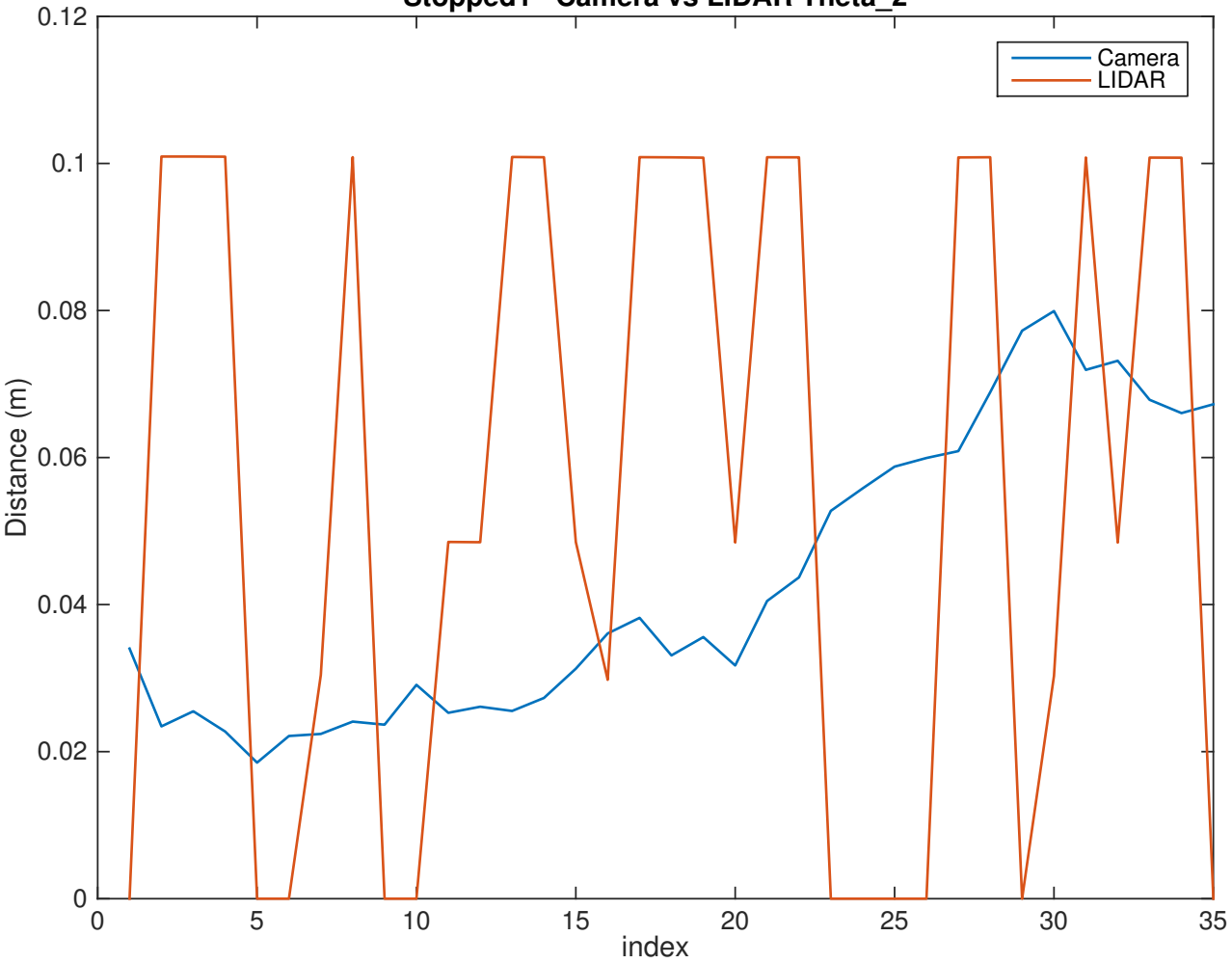
Stopped1 LIDAR Theta_1 vs Theta_2



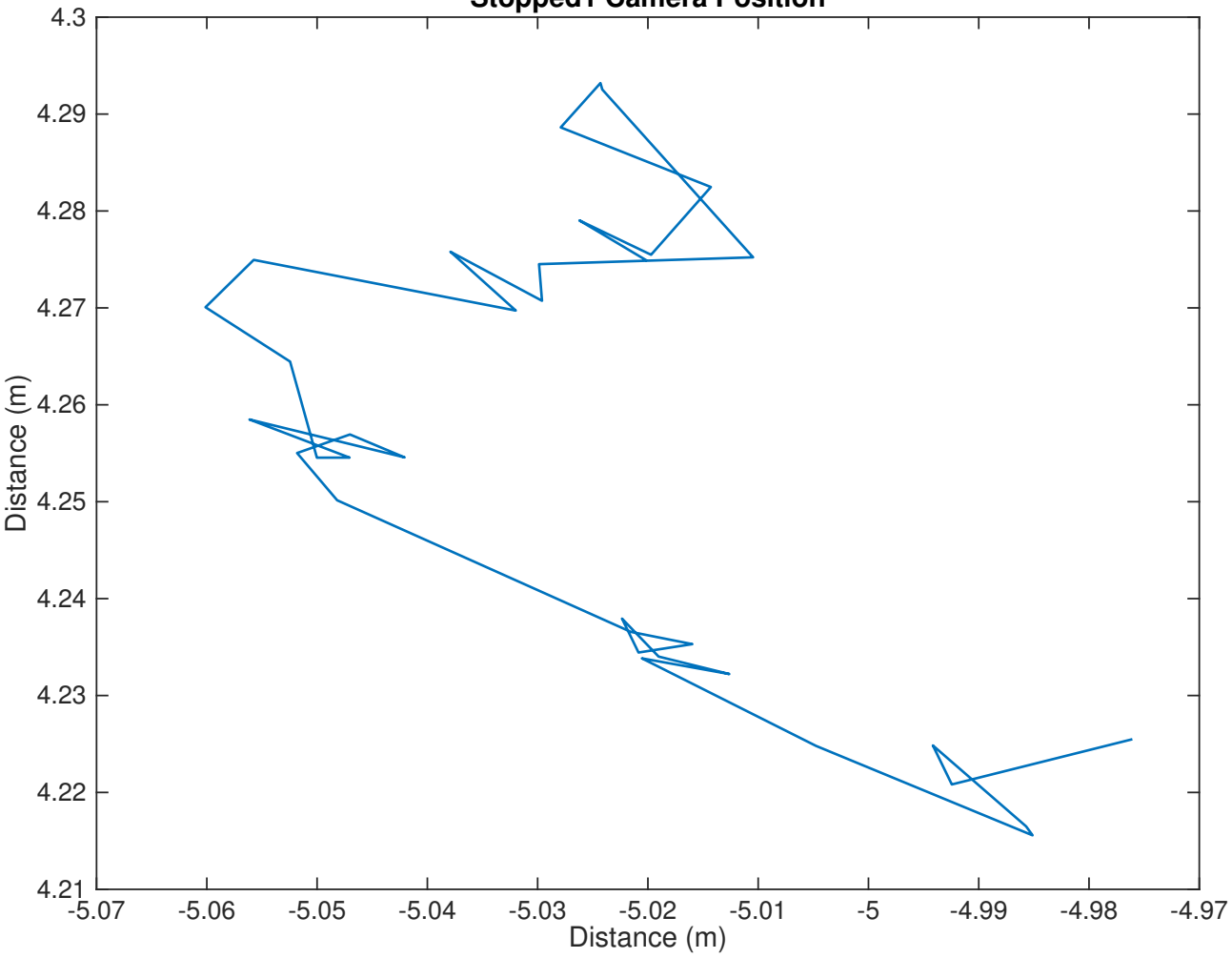
Stopped1 Camera vs LIDAR Theta_1



Stopped1 Camera vs LIDAR Theta_2

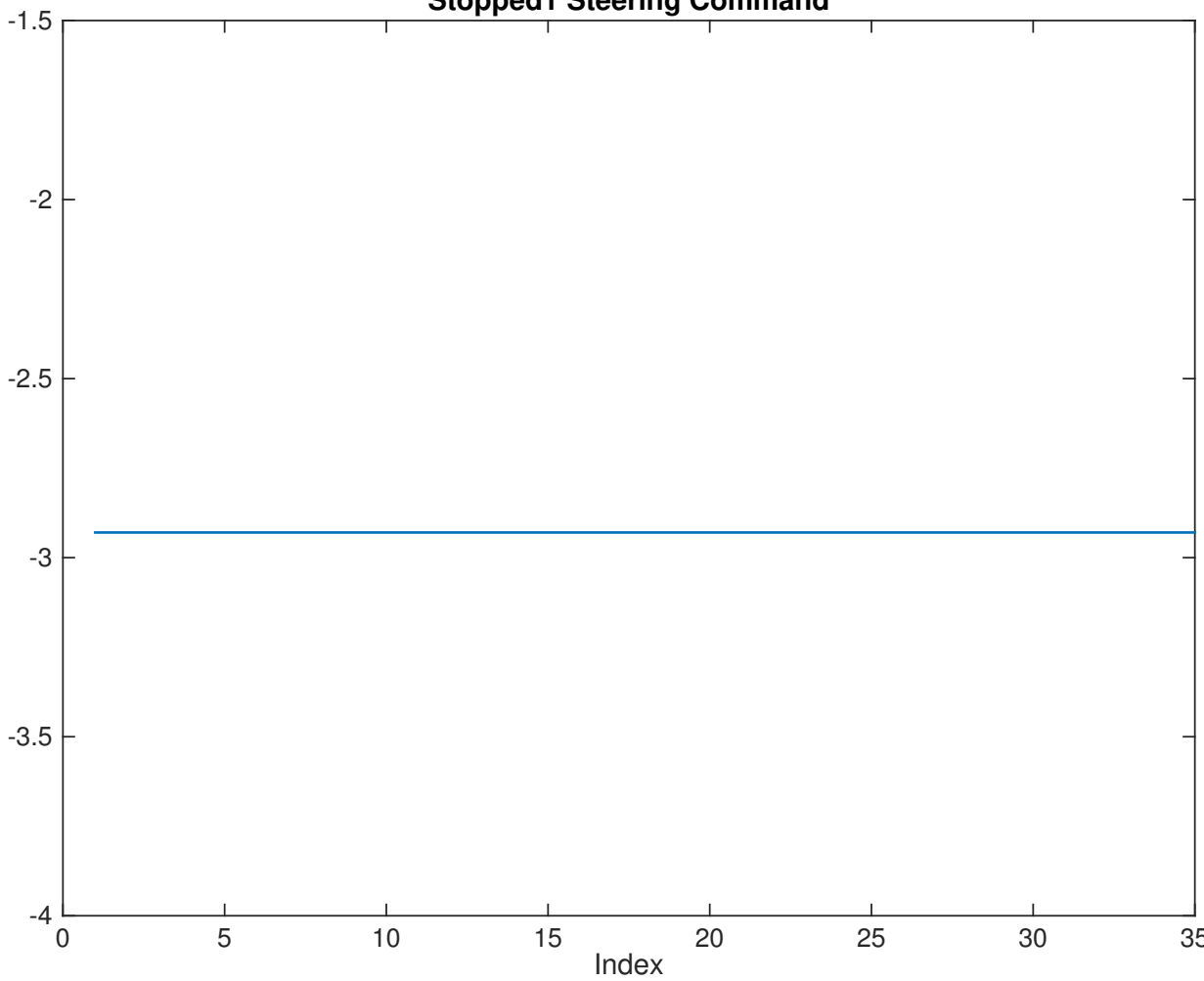


Stopped1 Camera Position

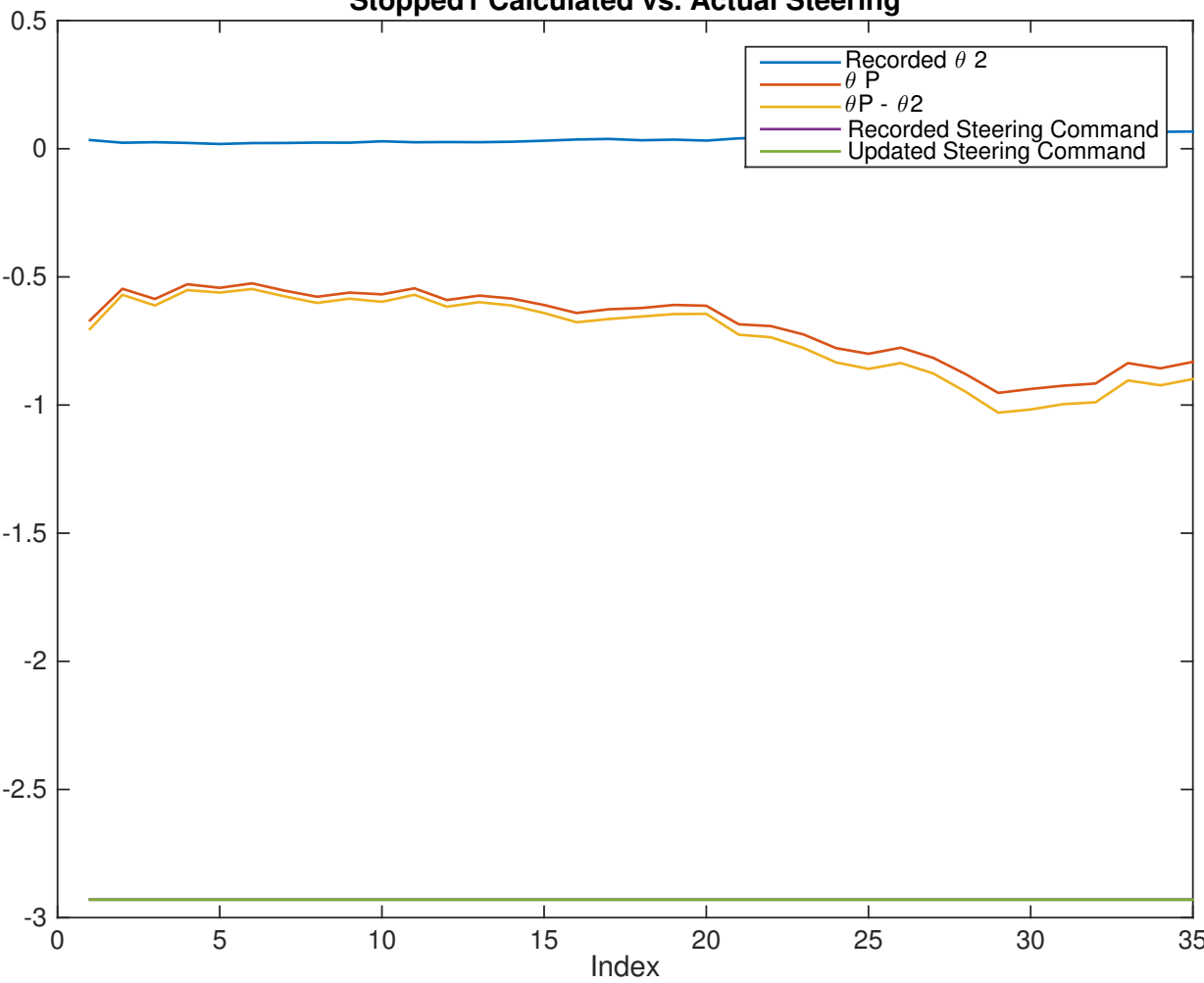


Stopped1 Steering Command

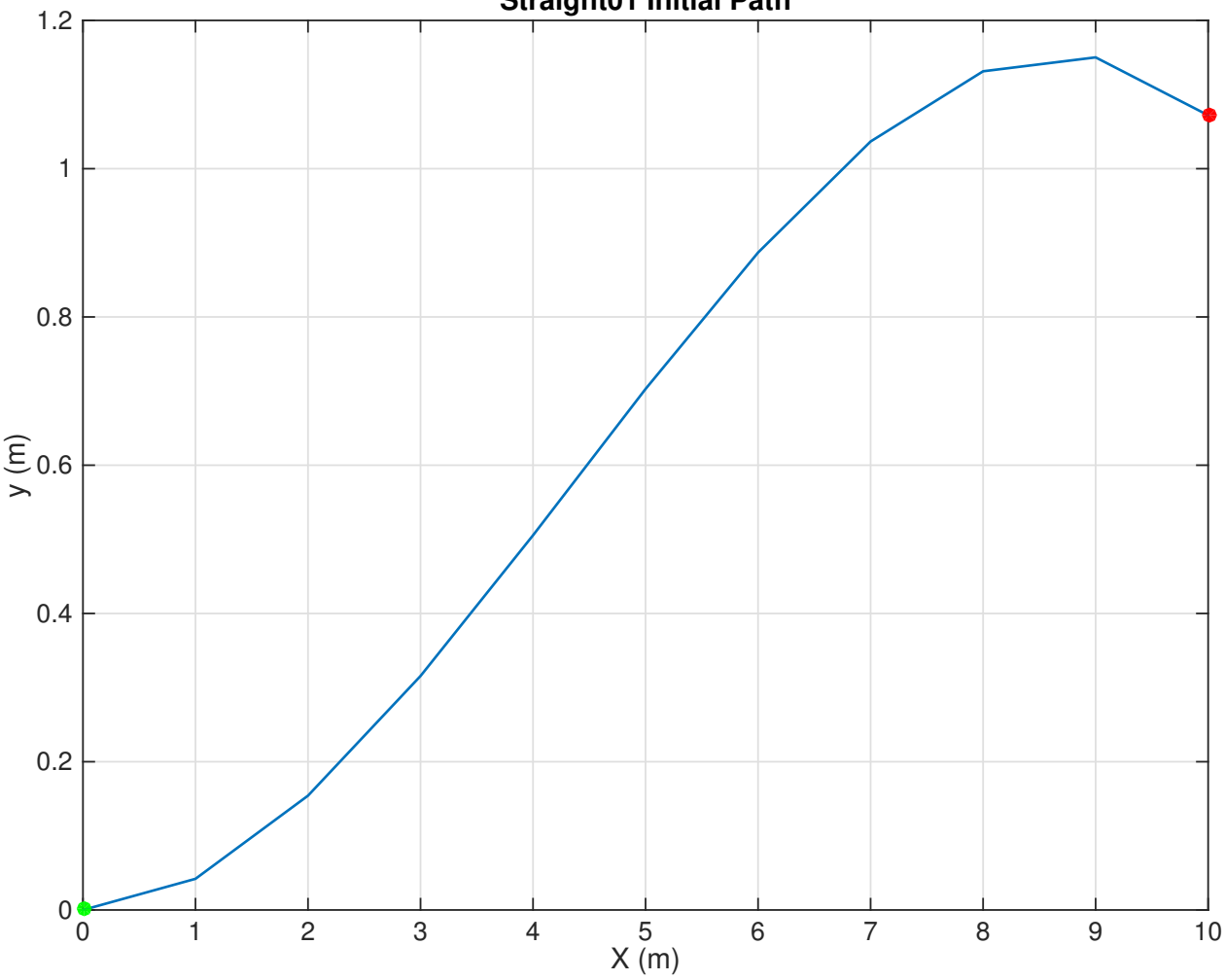
Turns (Clockwise Positive) 1 = 360° turn



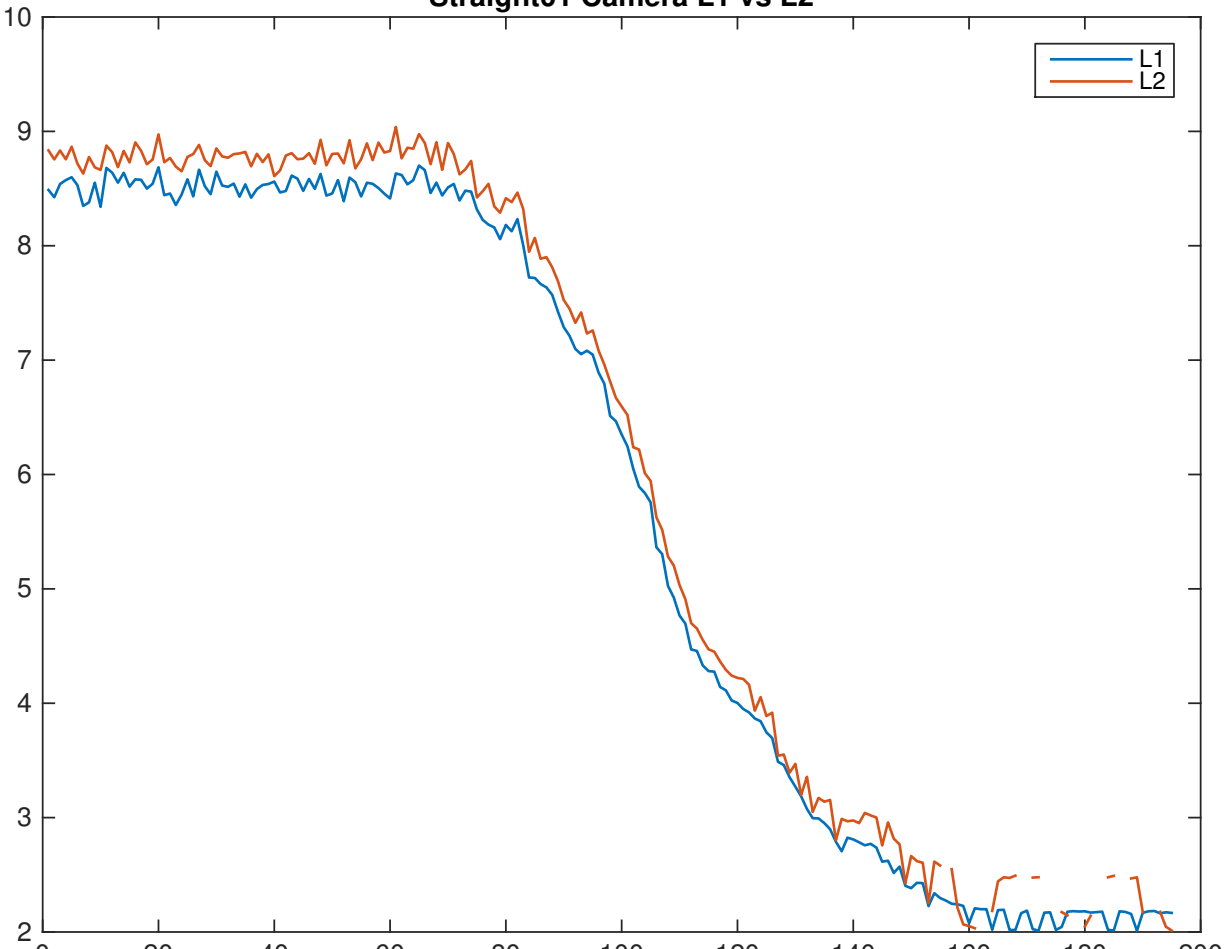
Stopped1 Calculated vs. Actual Steering



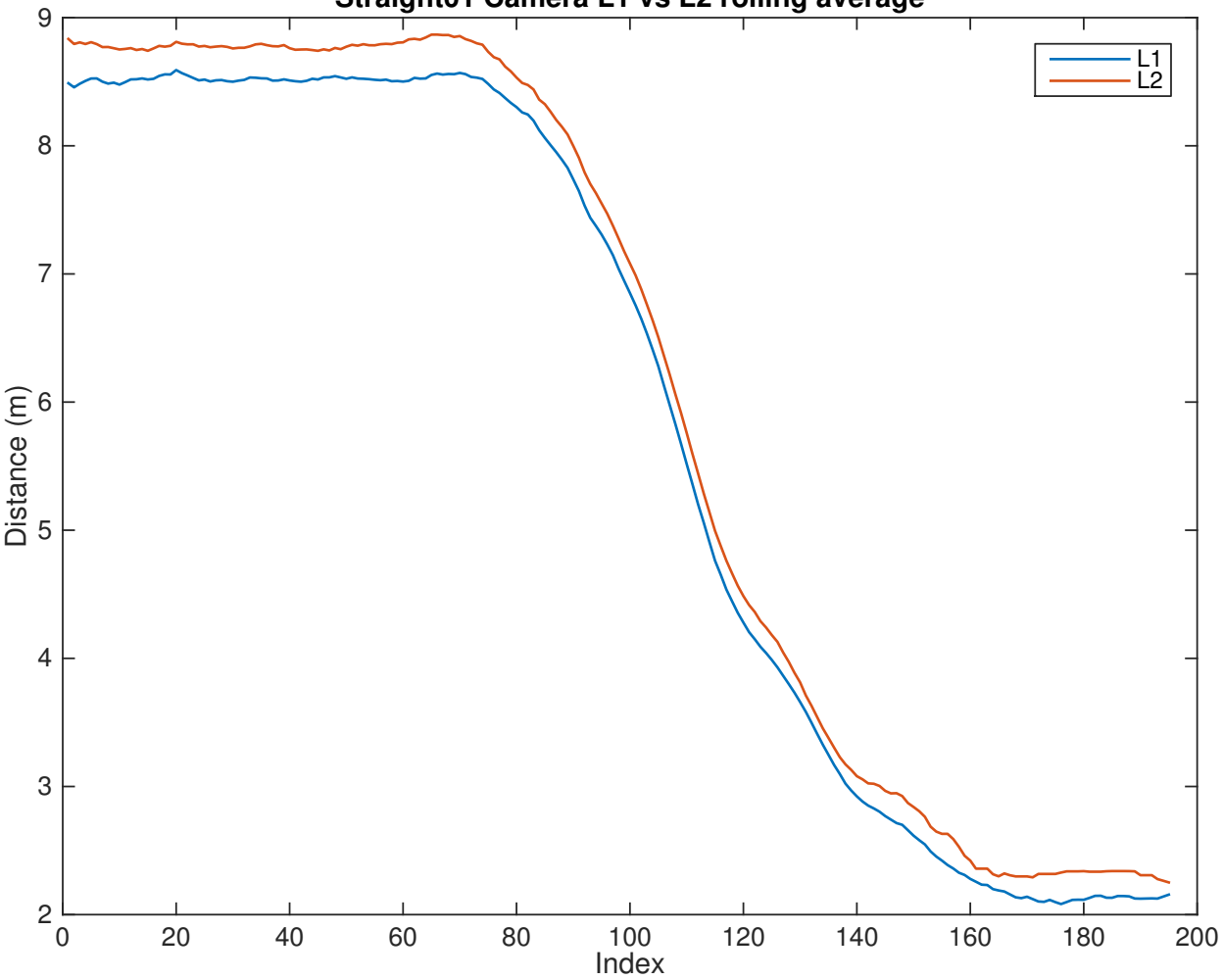
Straight01 Initial Path



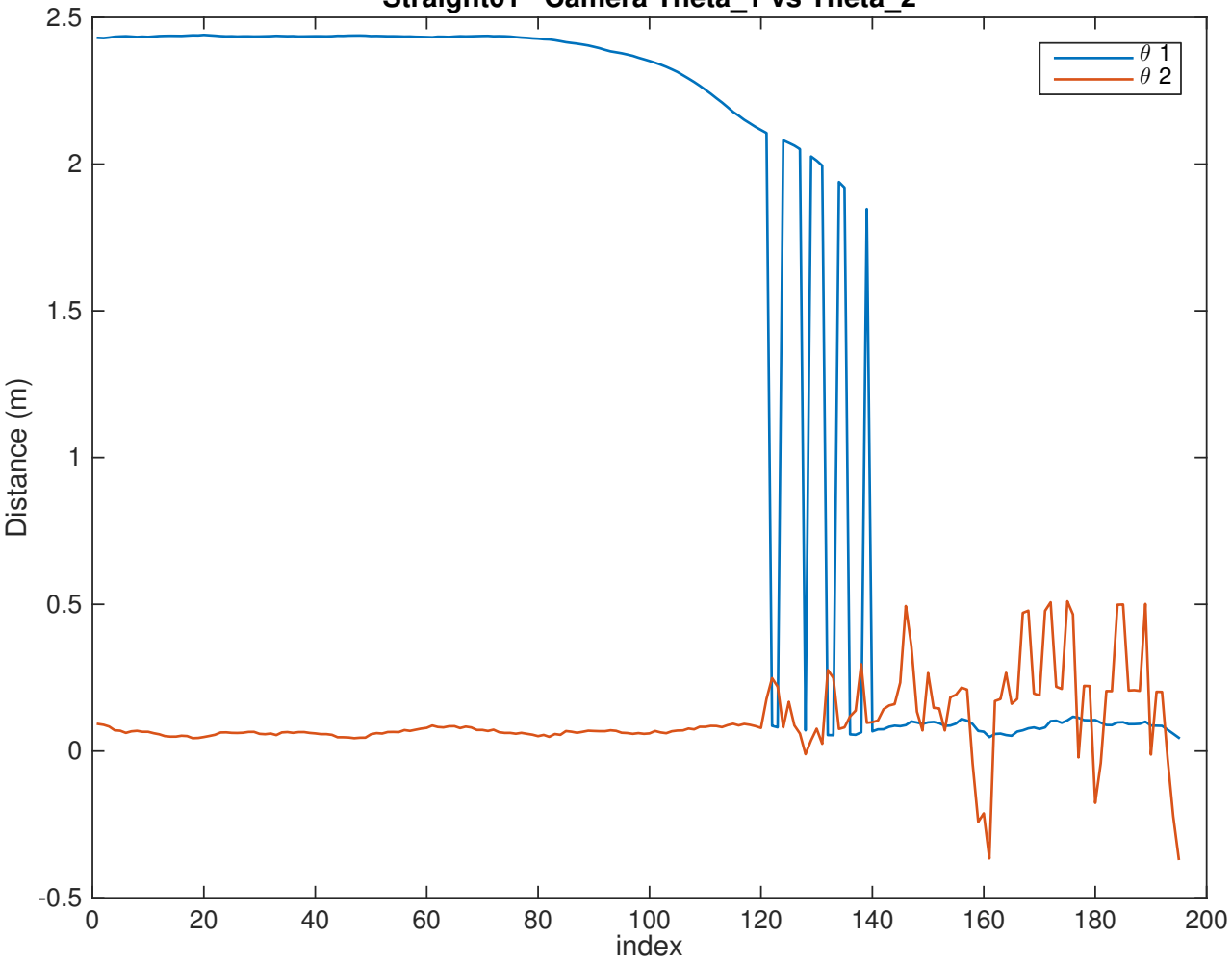
Straight01 Camera L1 vs L2



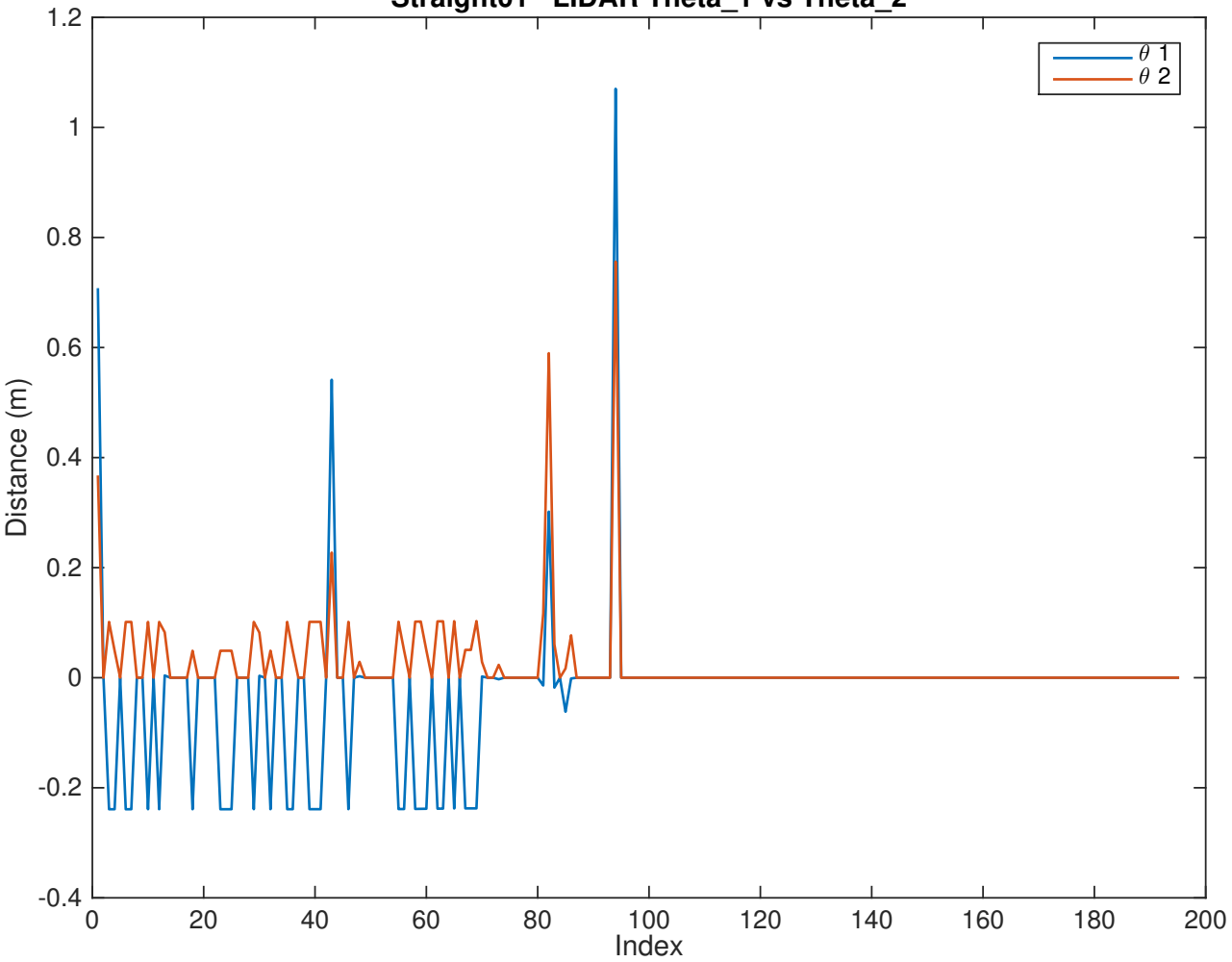
Straight01 Camera L1 vs L2 rolling average



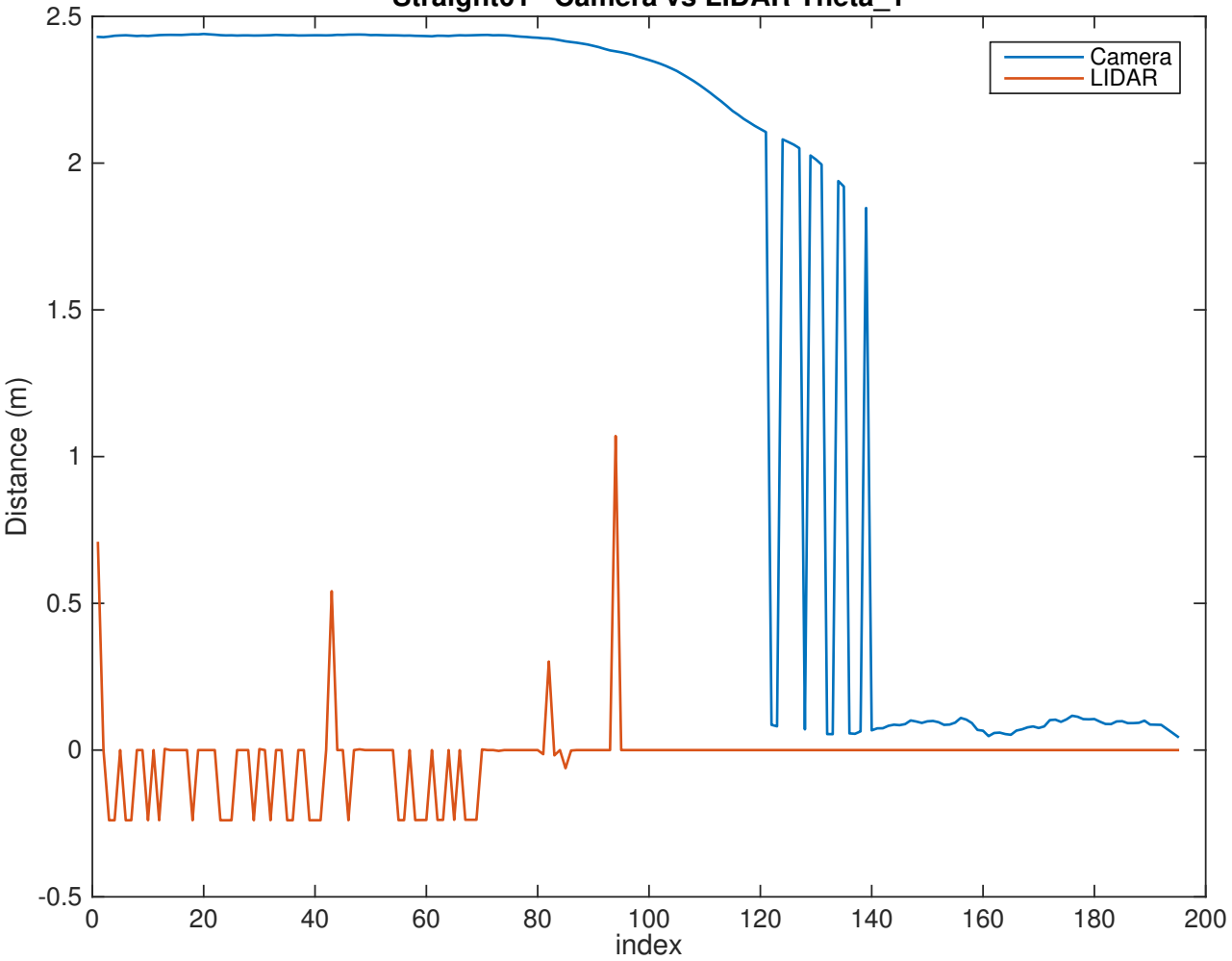
Straight01 Camera Theta_1 vs Theta_2



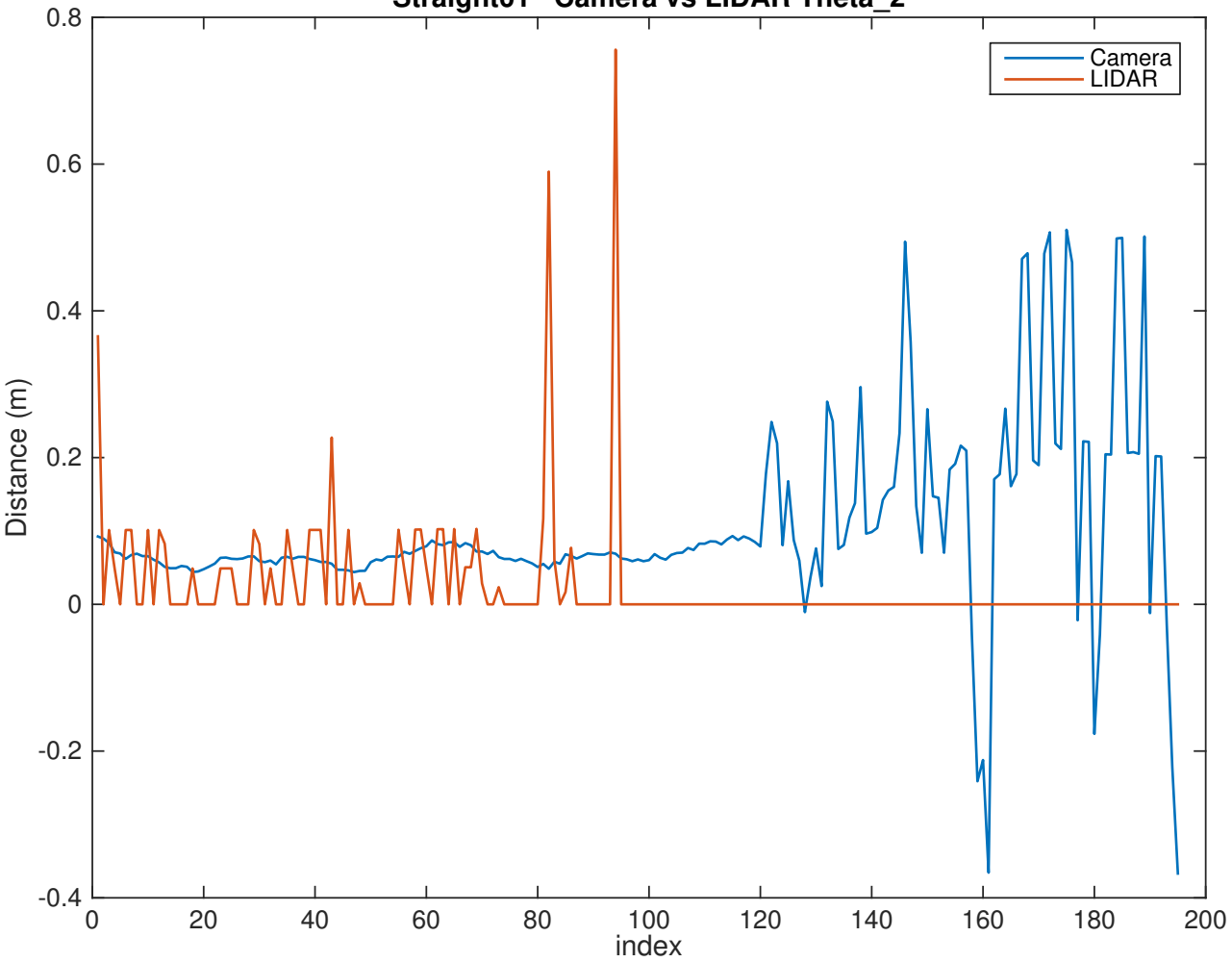
Straight01 LIDAR Theta_1 vs Theta_2



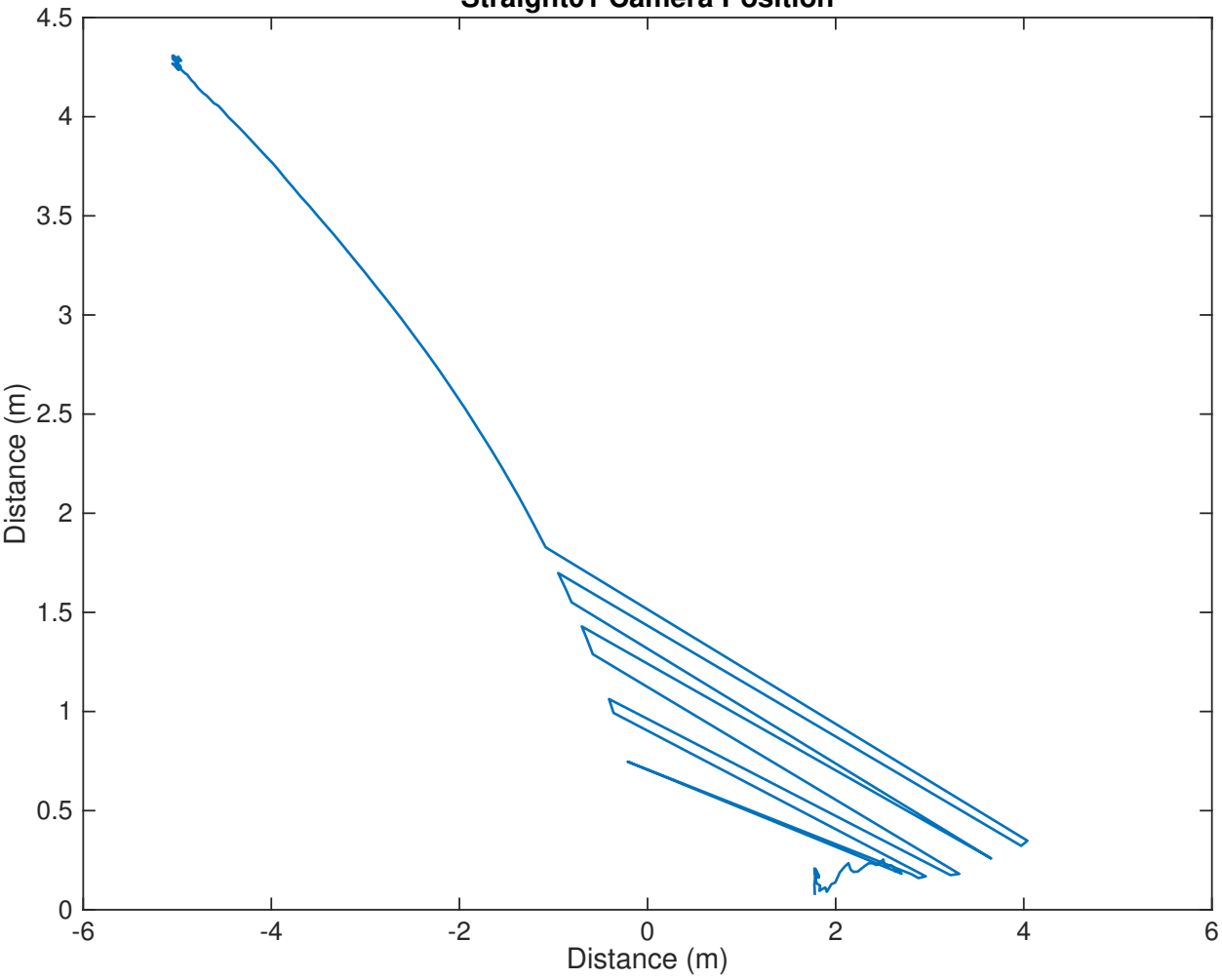
Straight01 Camera vs LIDAR Theta_1



Straight01 Camera vs LIDAR Theta_2

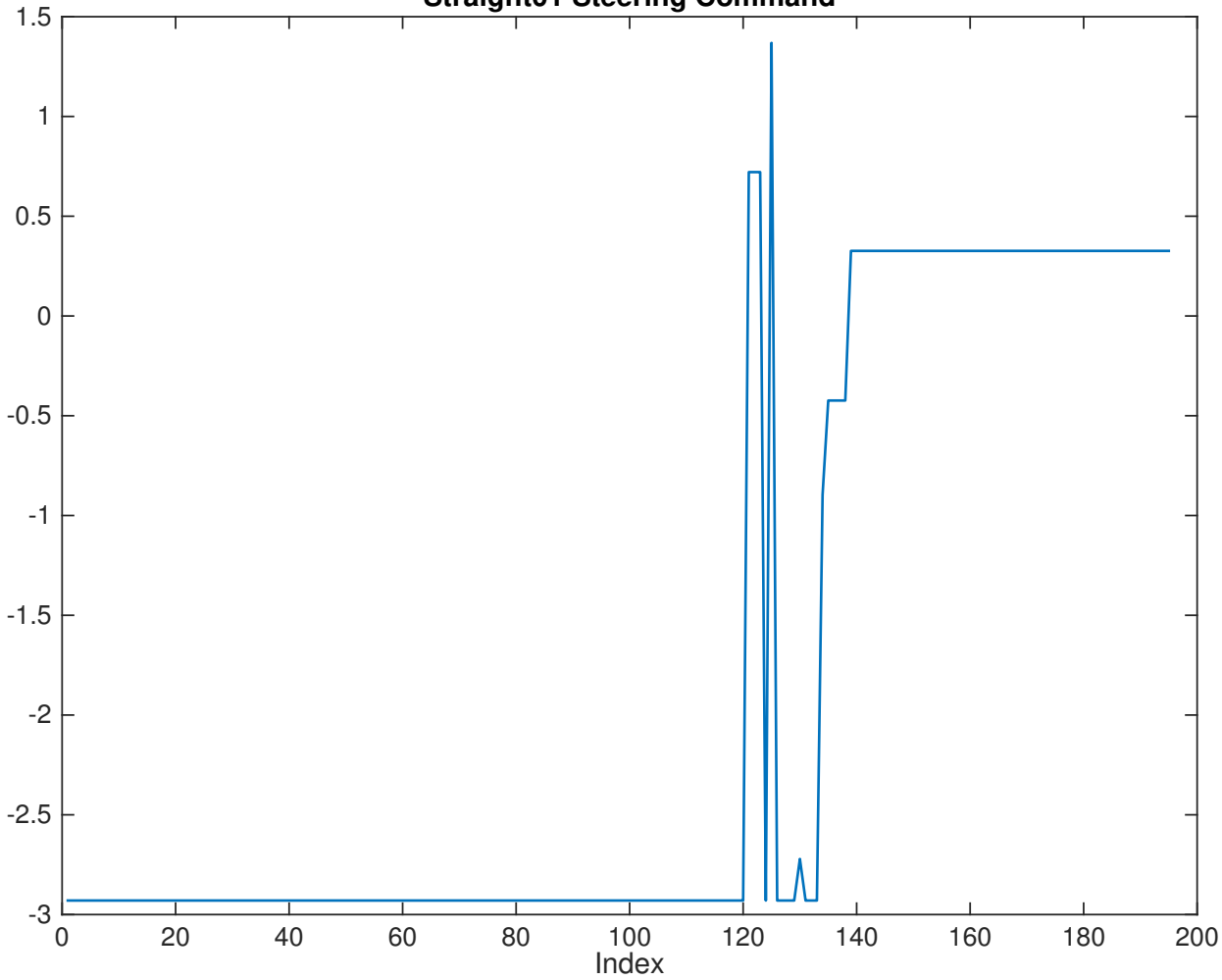


Straight01 Camera Position

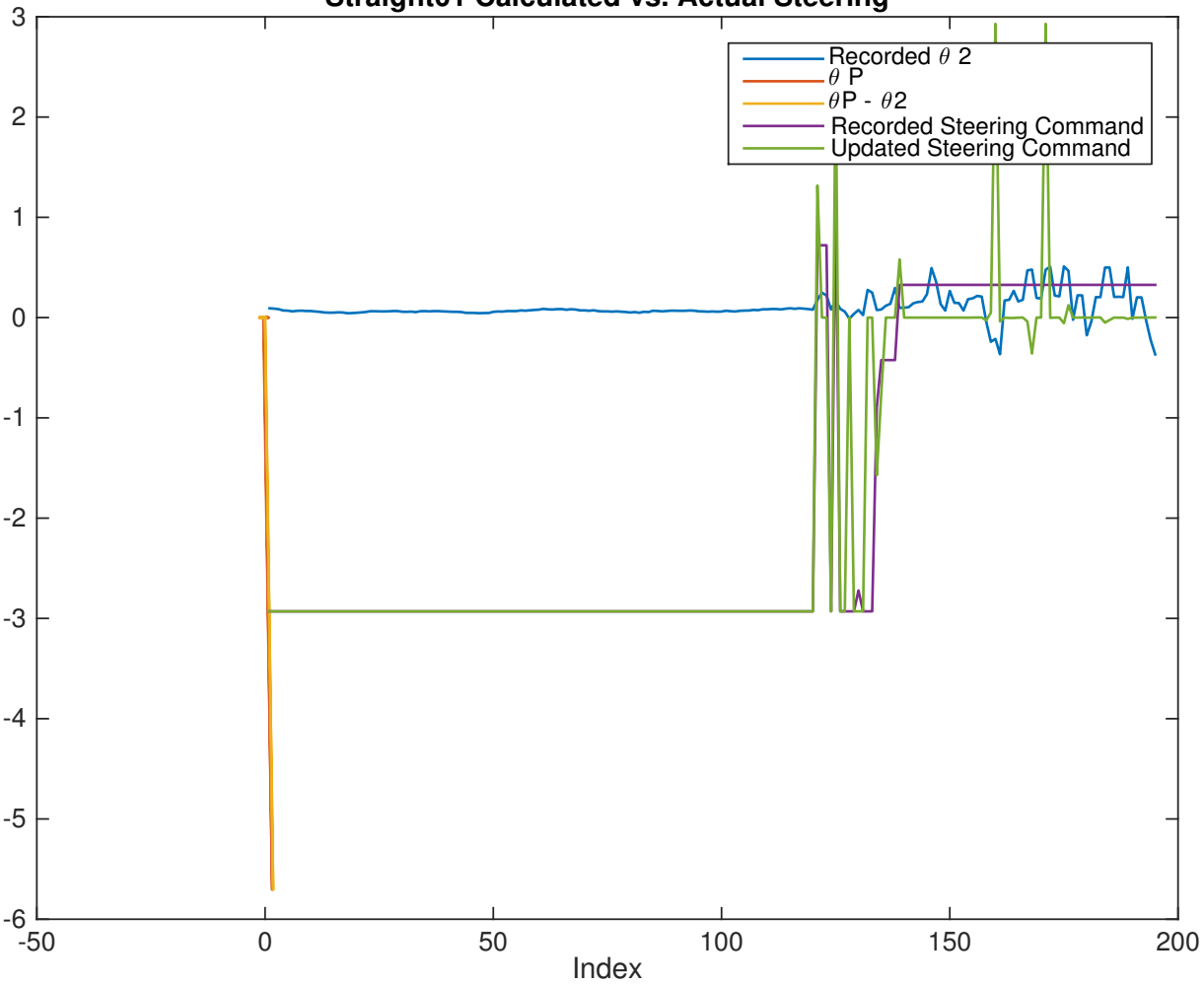


Straight01 Steering Command

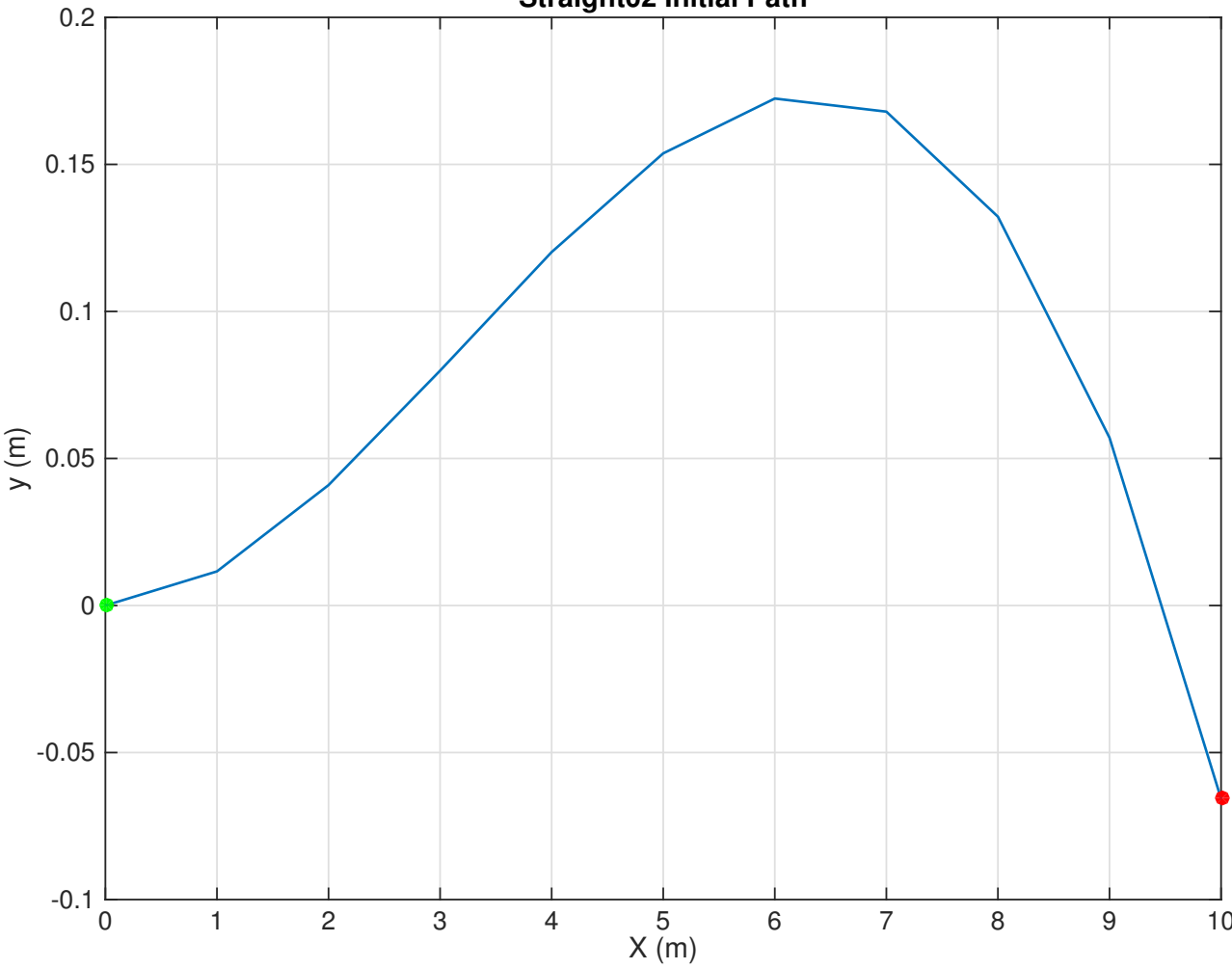
Turns (Clockwise Positive) 1 = 360° turn



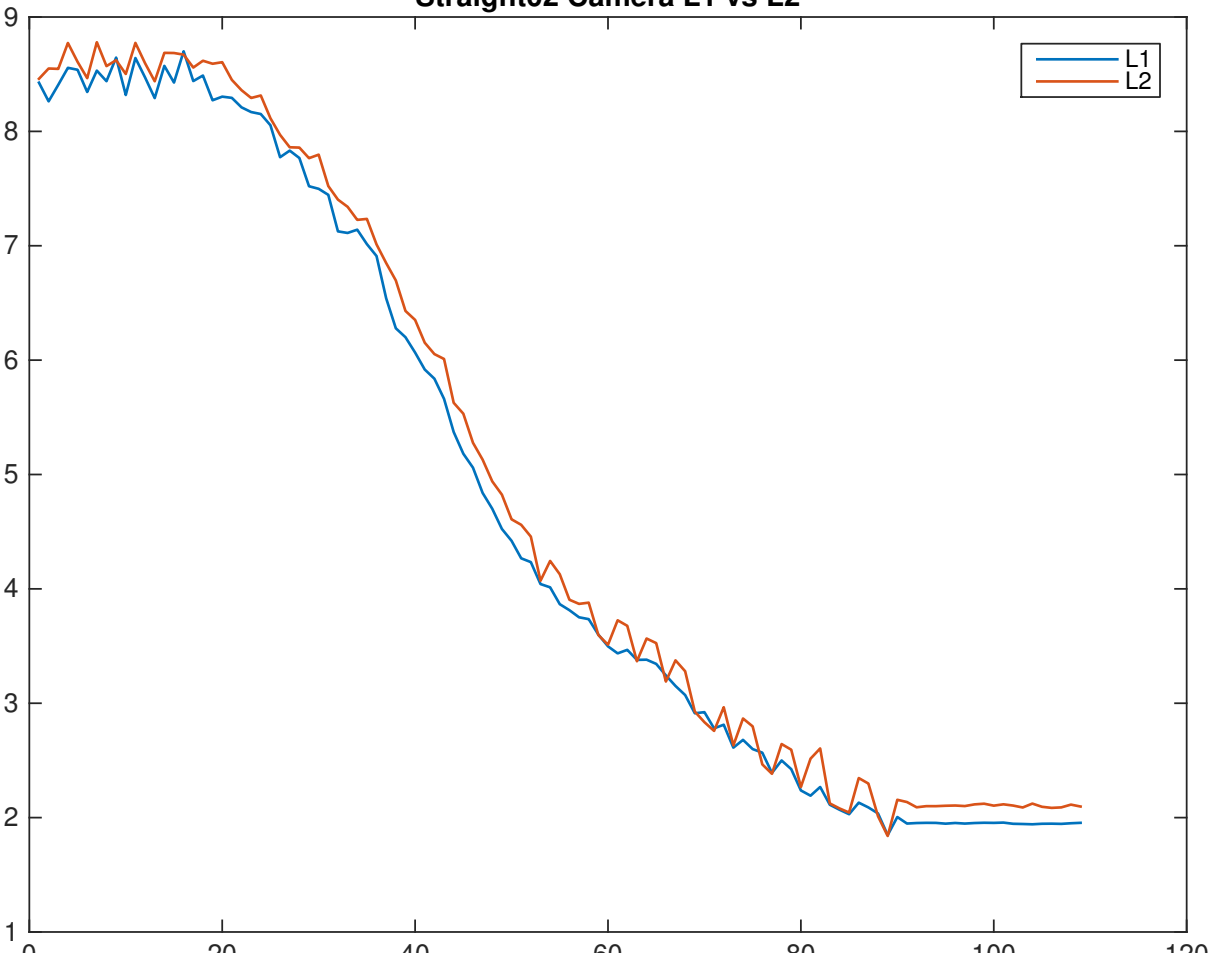
Straight01 Calculated vs. Actual Steering



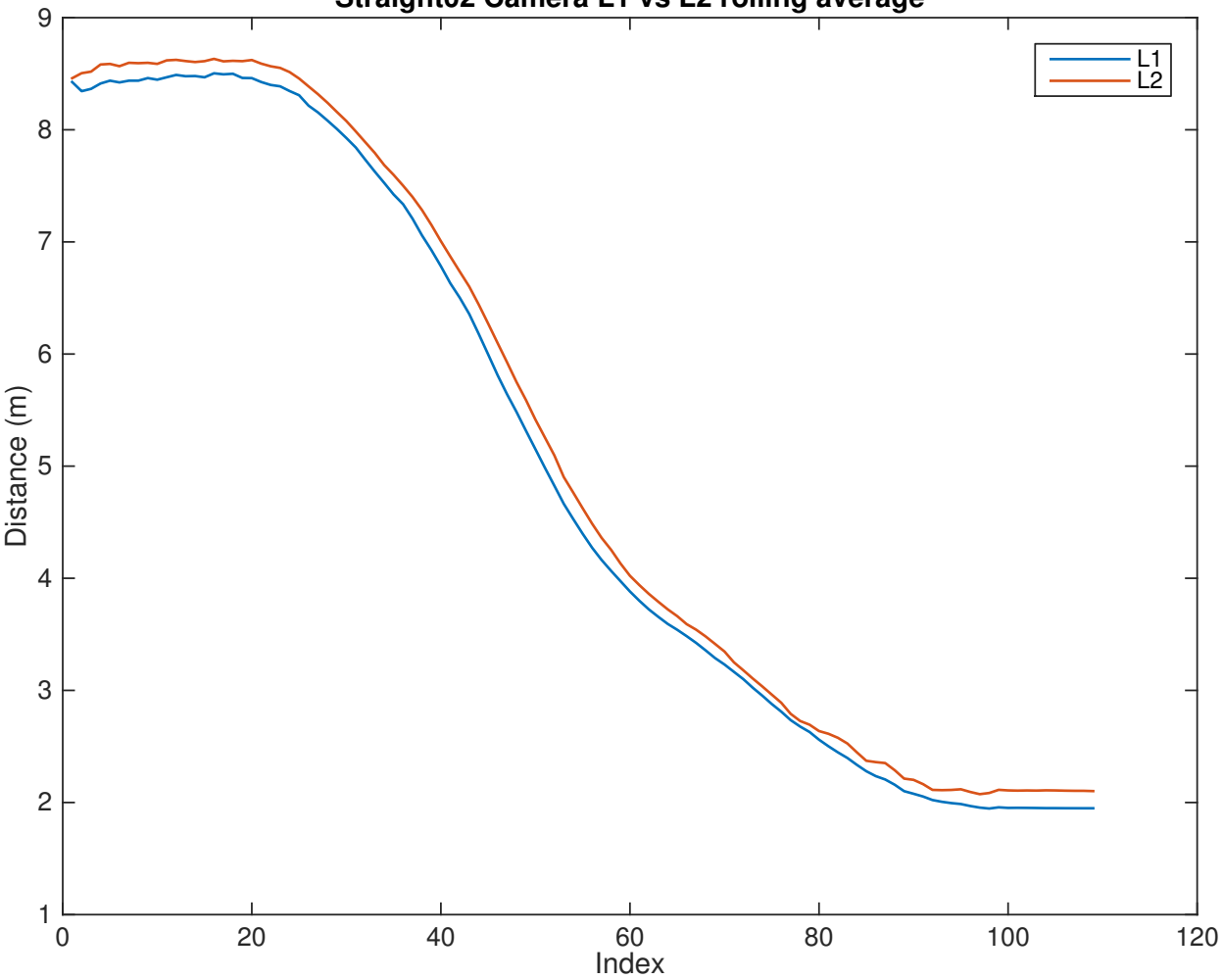
Straight02 Initial Path



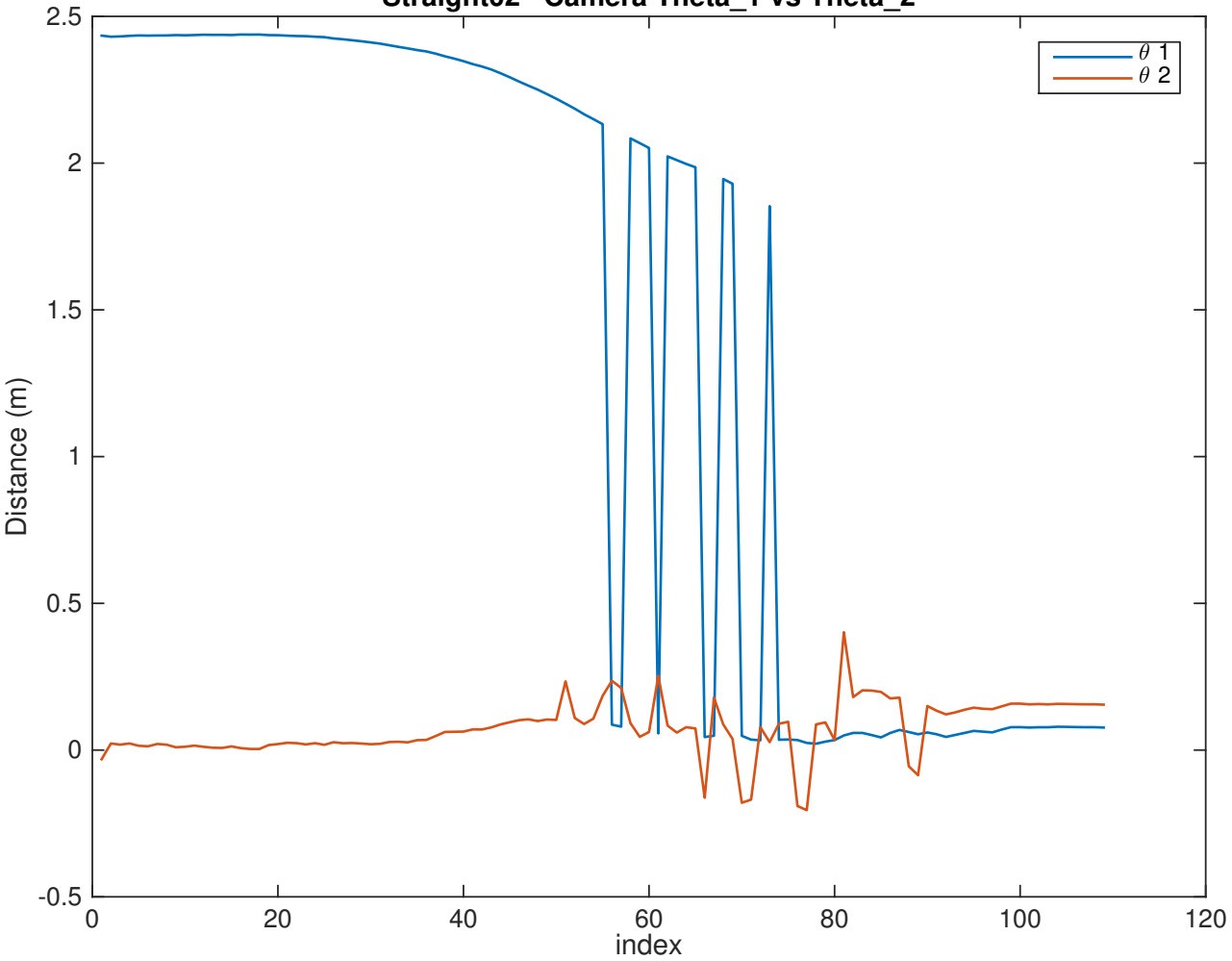
Straight02 Camera L1 vs L2



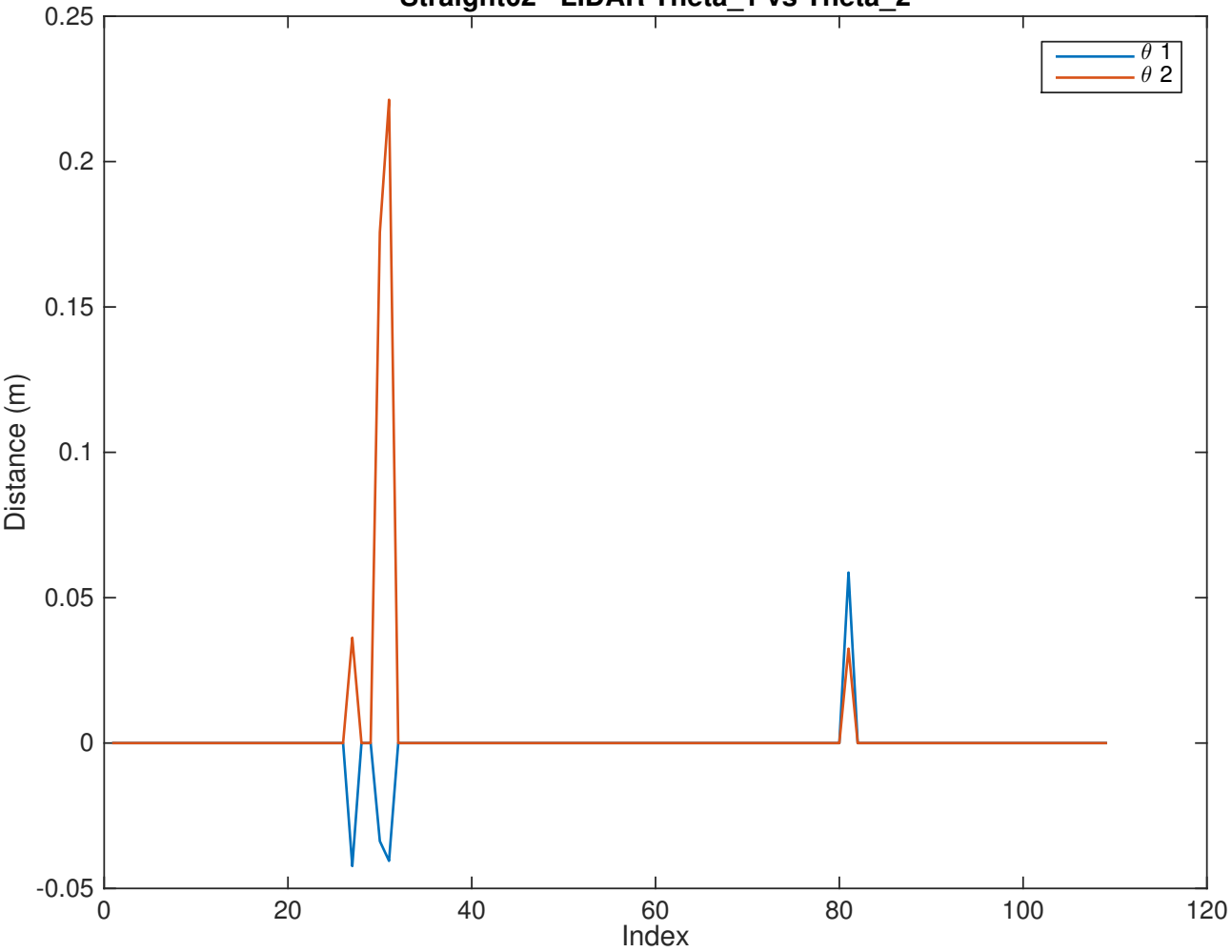
Straight02 Camera L1 vs L2 rolling average



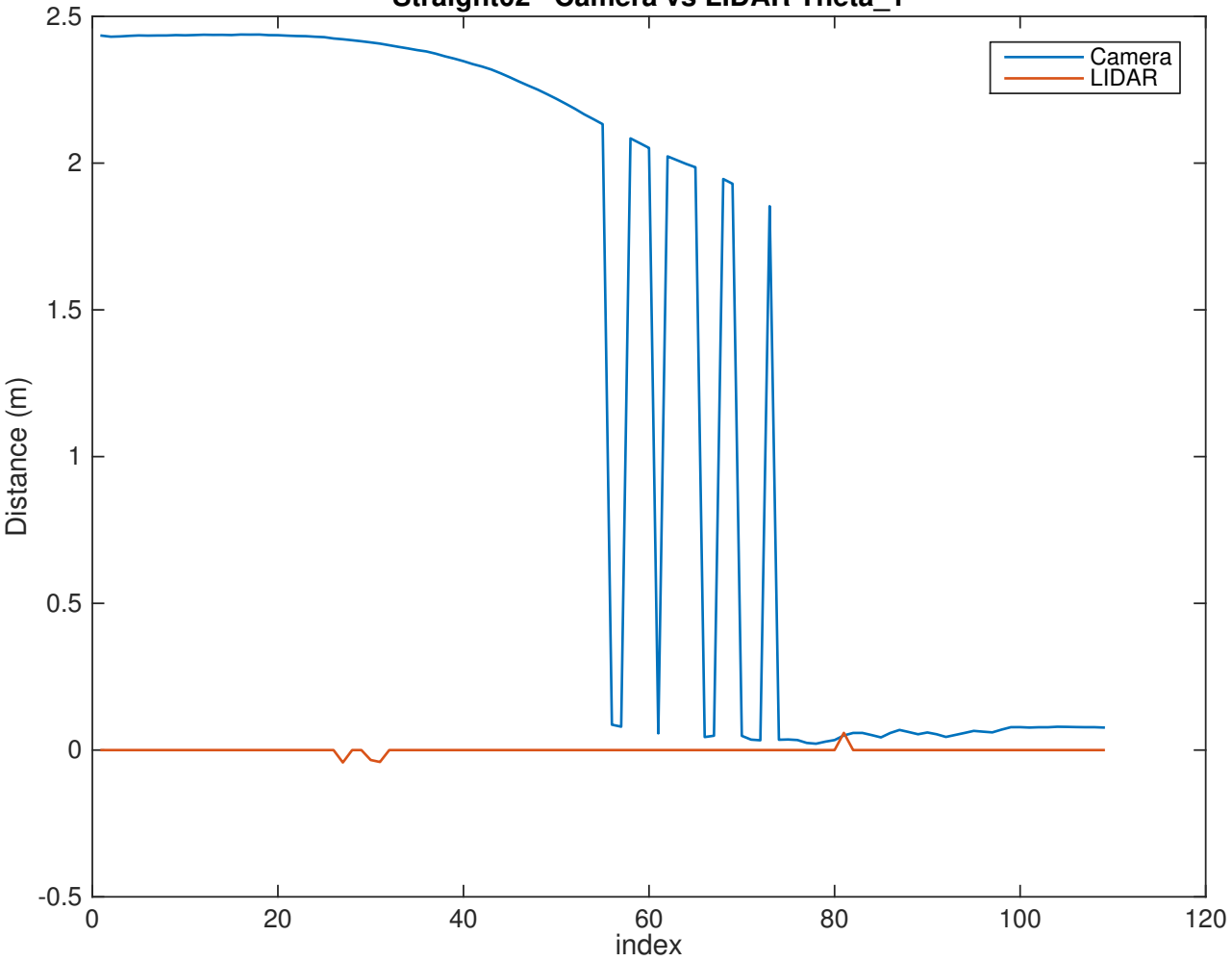
Straight02 Camera Theta_1 vs Theta_2



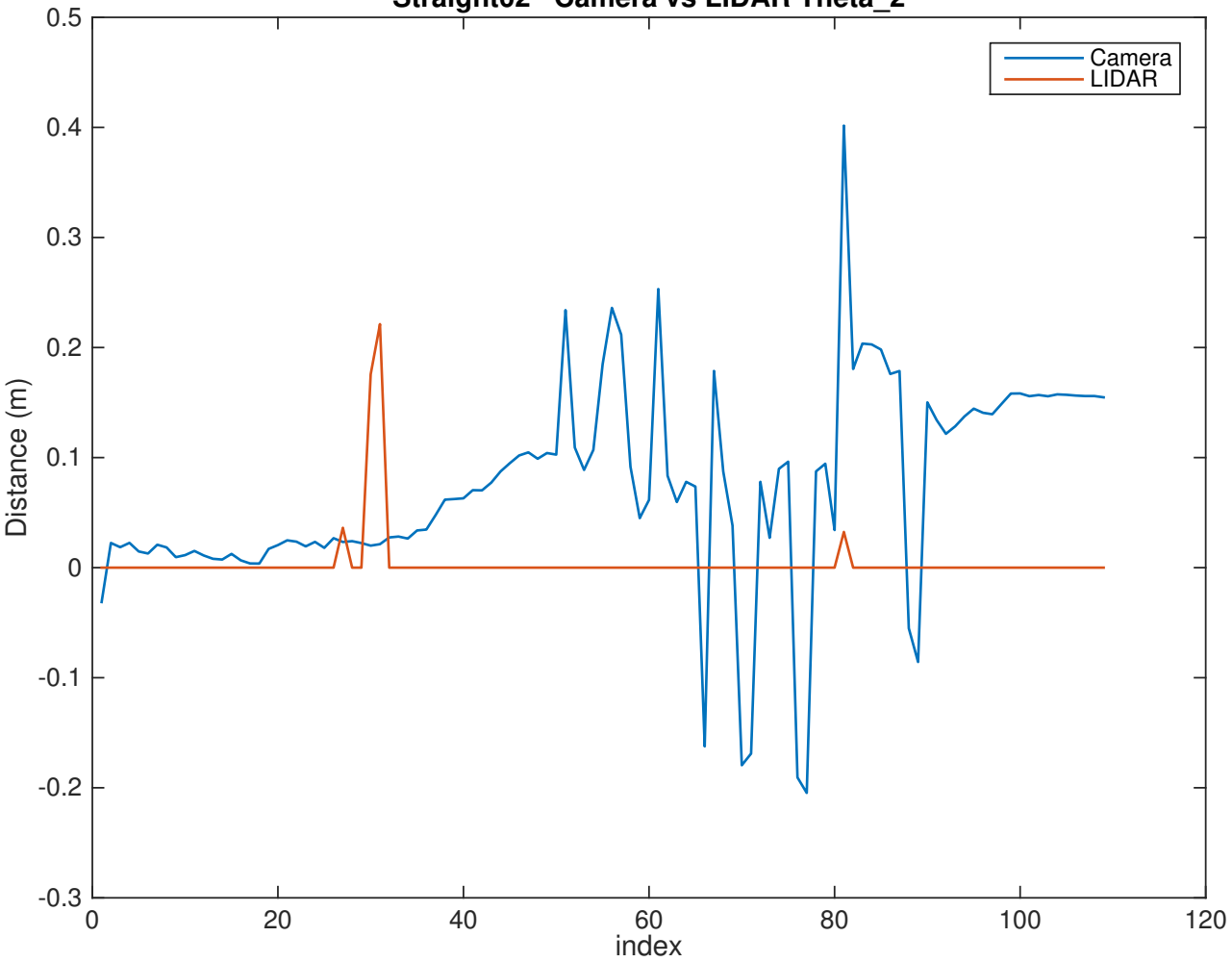
Straight02 LIDAR Theta_1 vs Theta_2



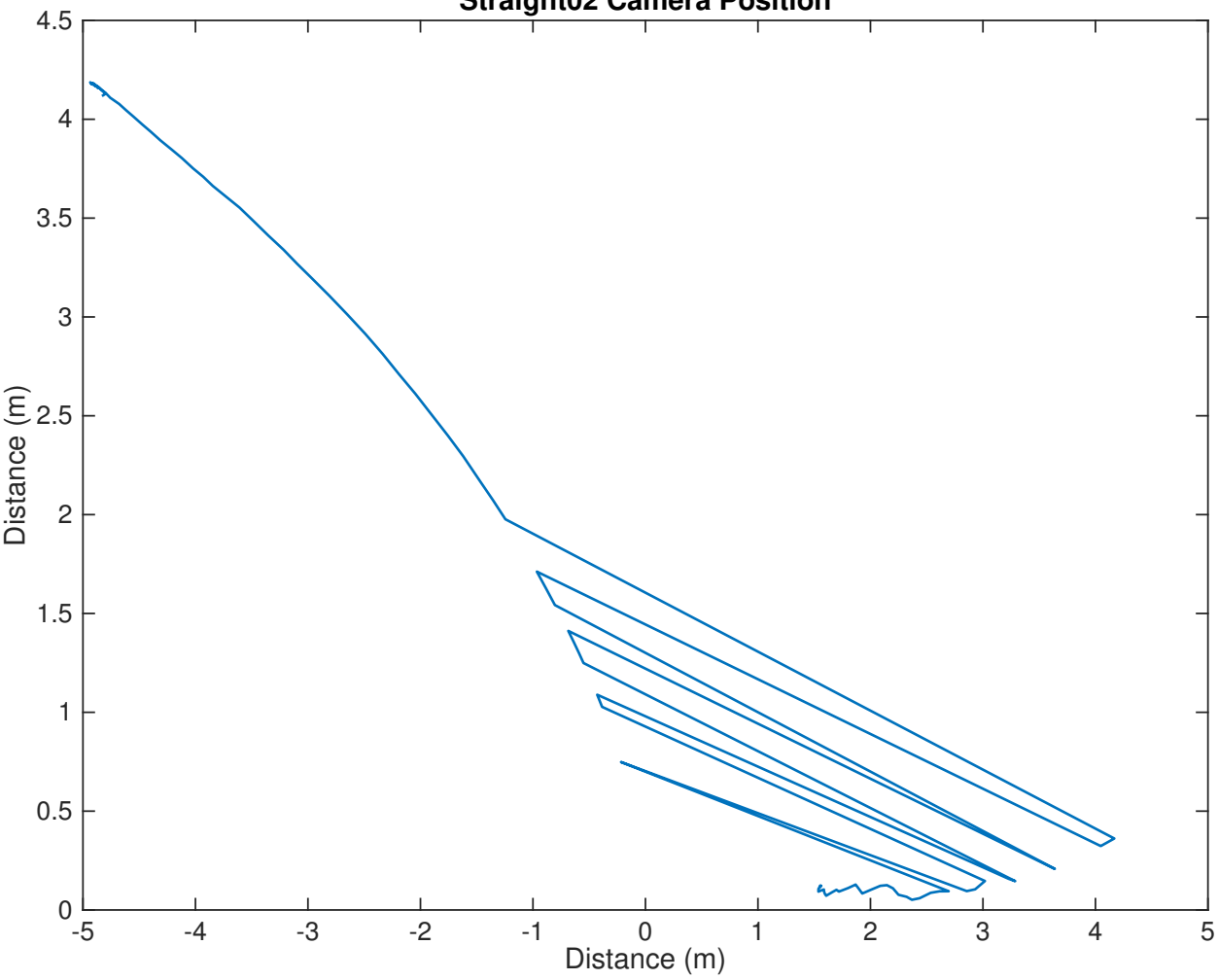
Straight02 Camera vs LIDAR Theta_1



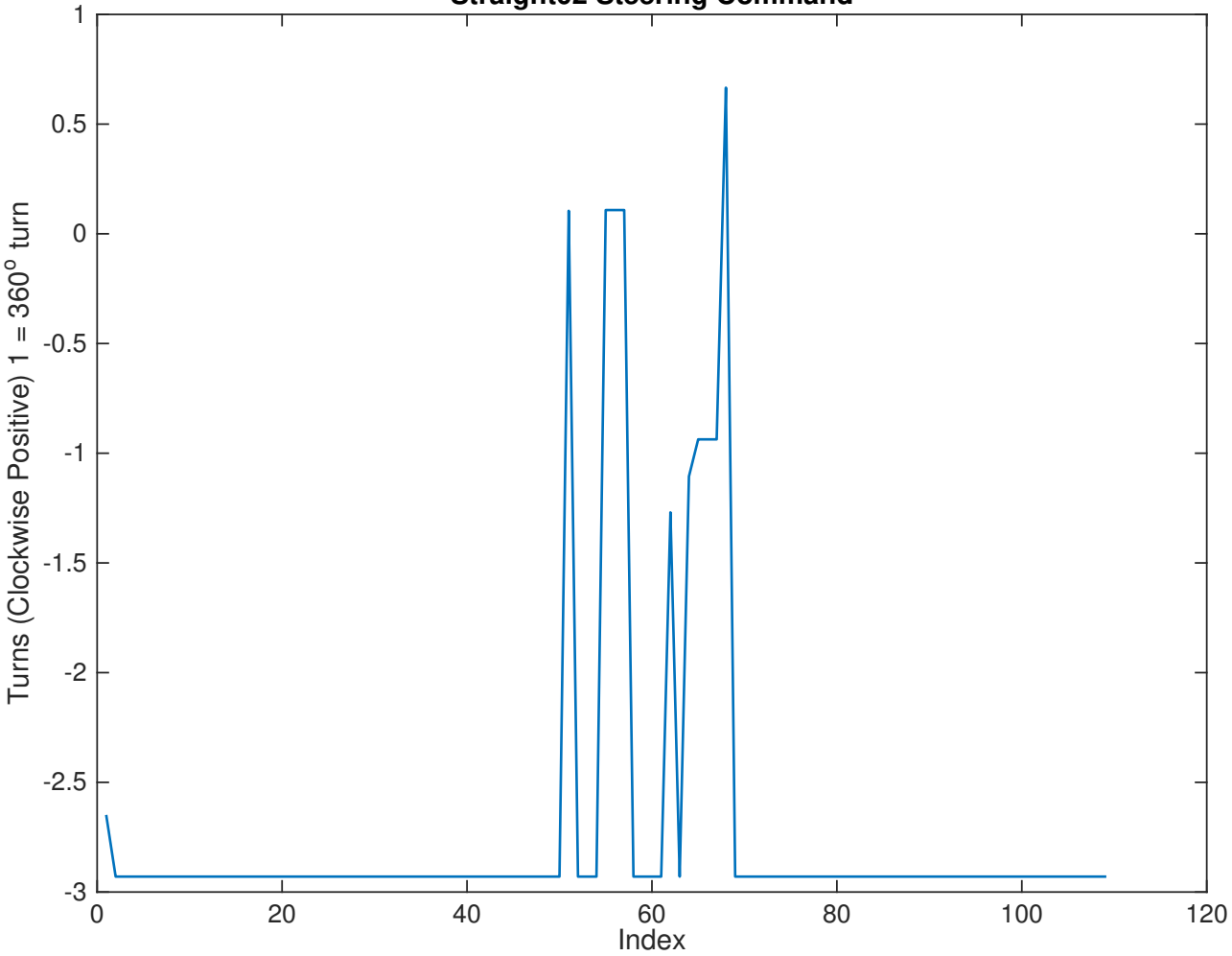
Straight02 Camera vs LIDAR Theta_2



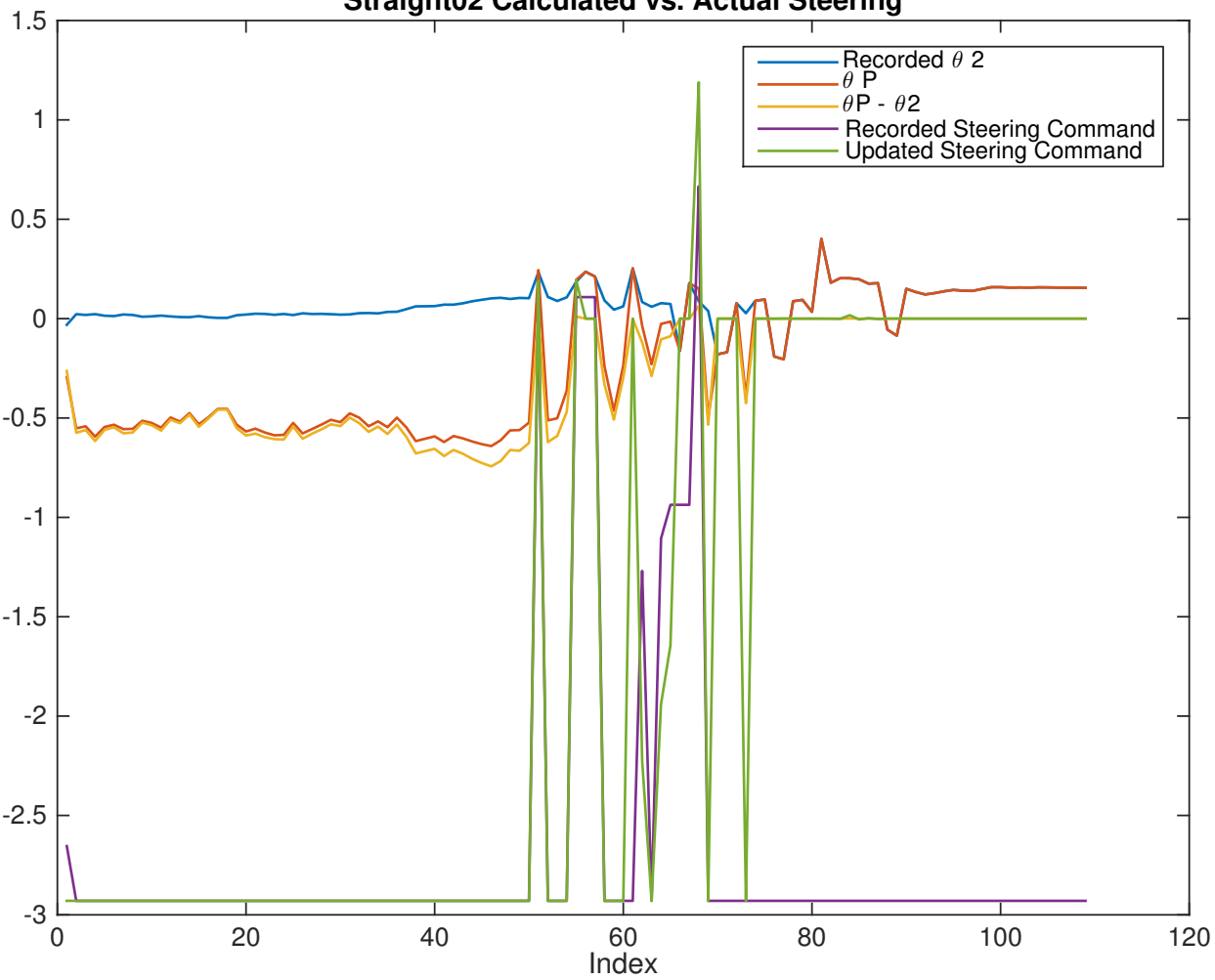
Straight02 Camera Position



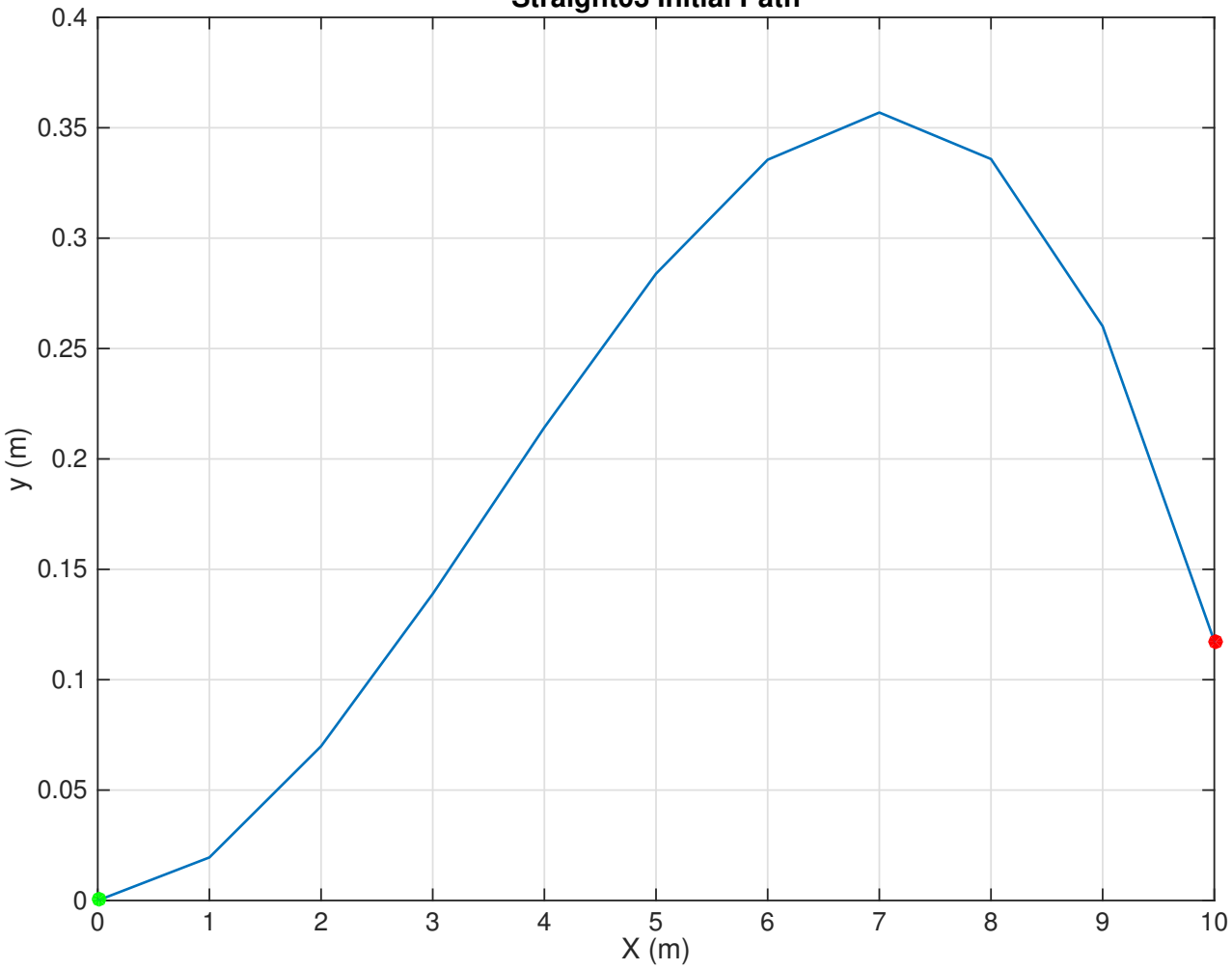
Straight02 Steering Command



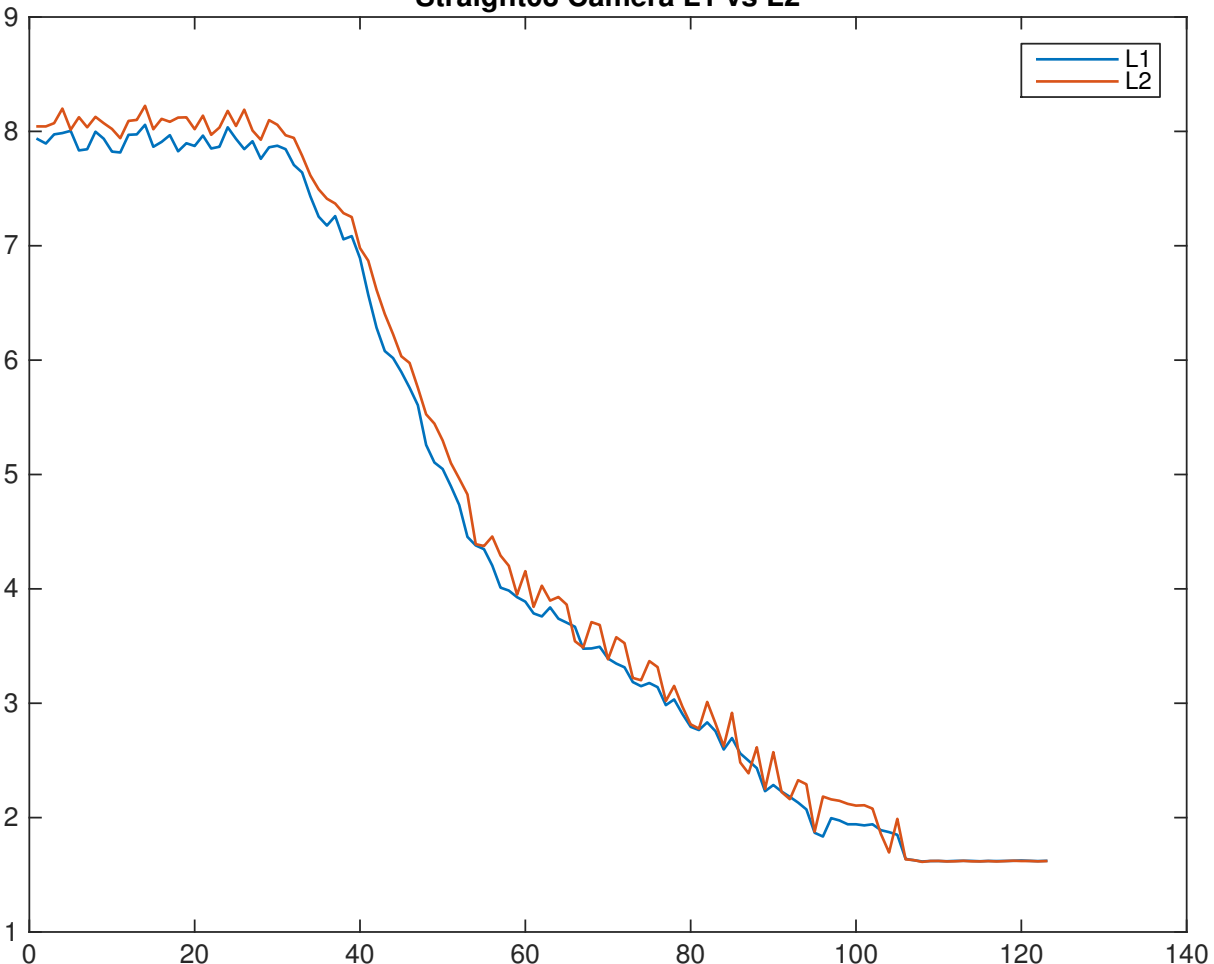
Straight02 Calculated vs. Actual Steering



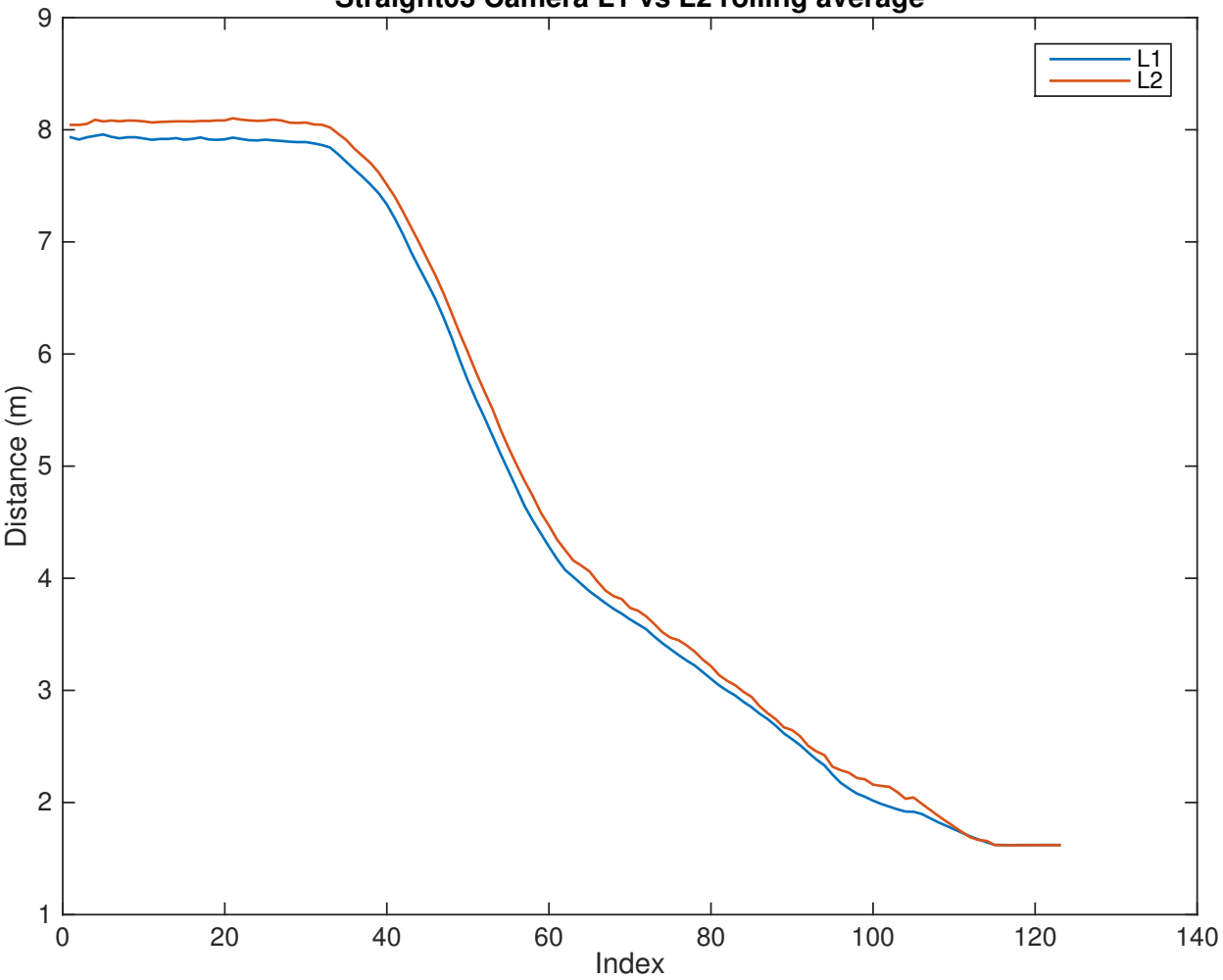
Straight03 Initial Path



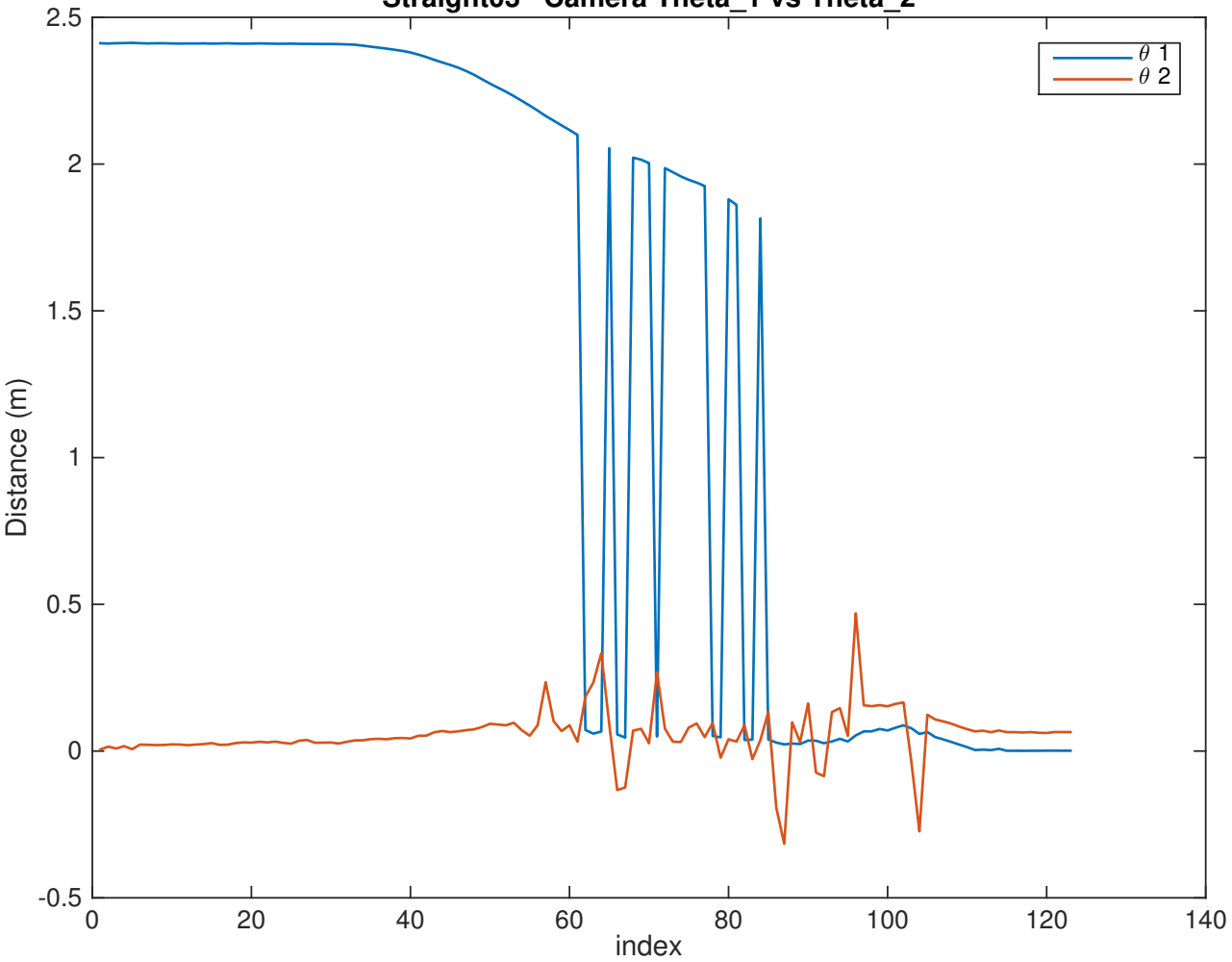
Straight03 Camera L1 vs L2



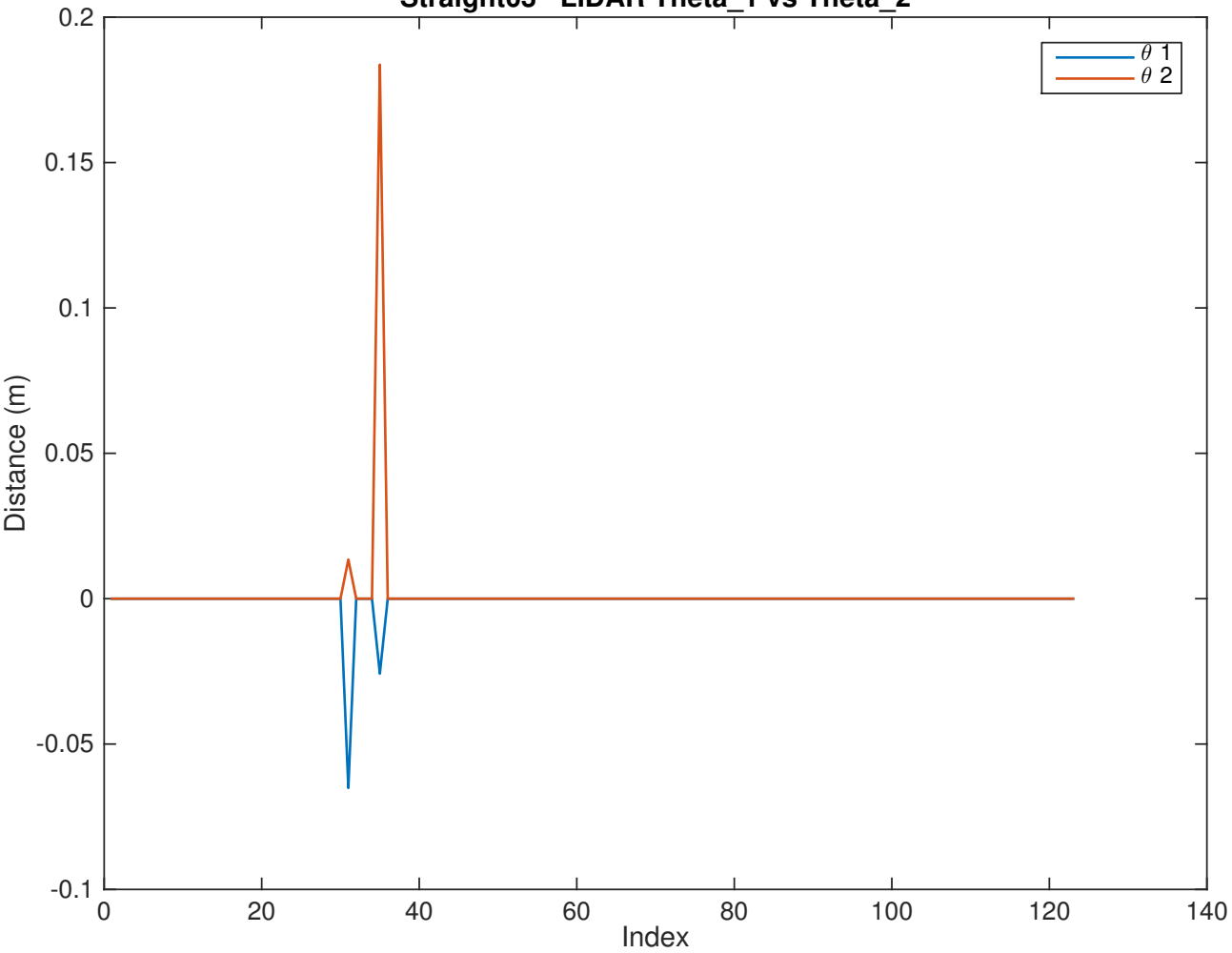
Straight03 Camera L1 vs L2 rolling average



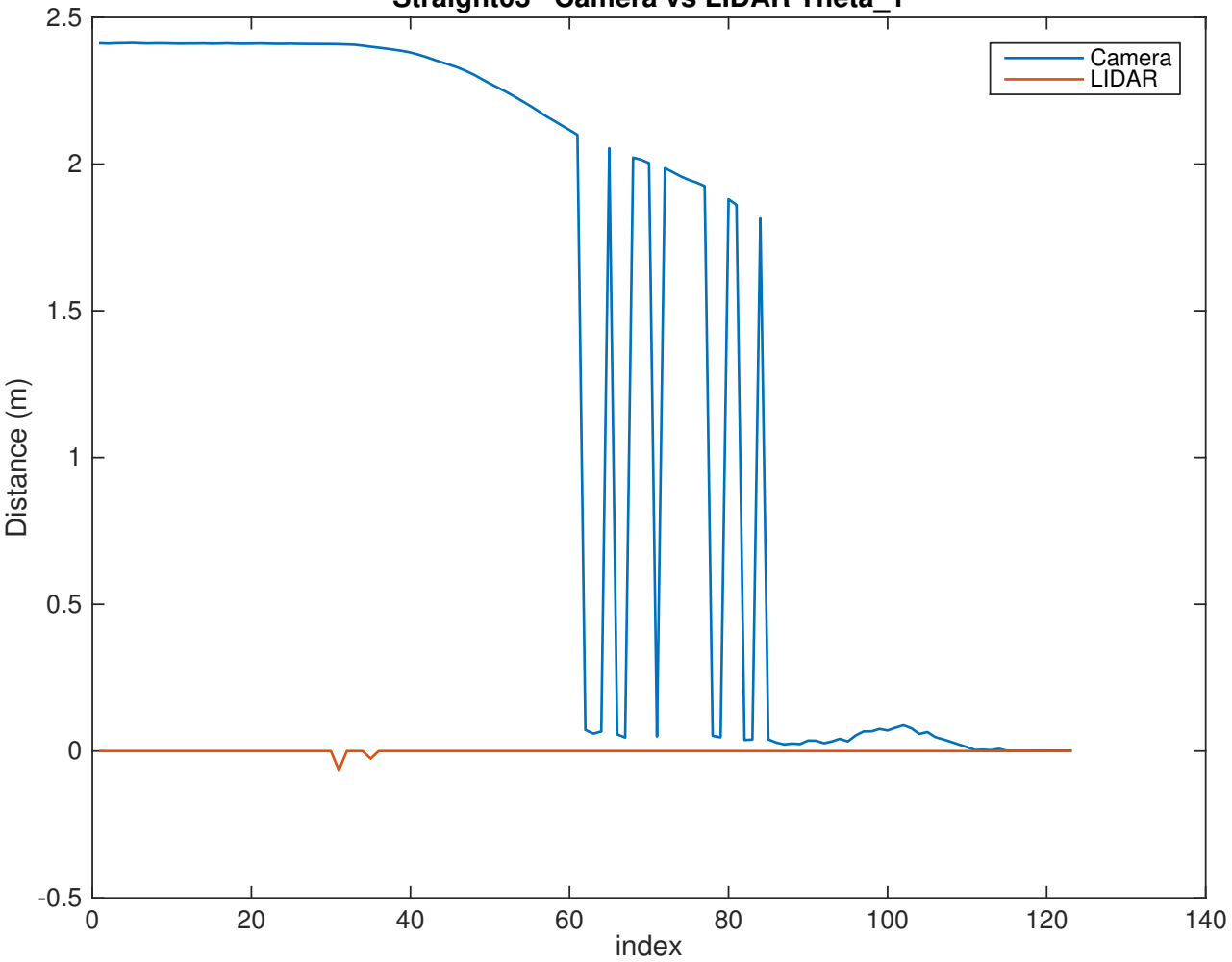
Straight03 Camera Theta_1 vs Theta_2



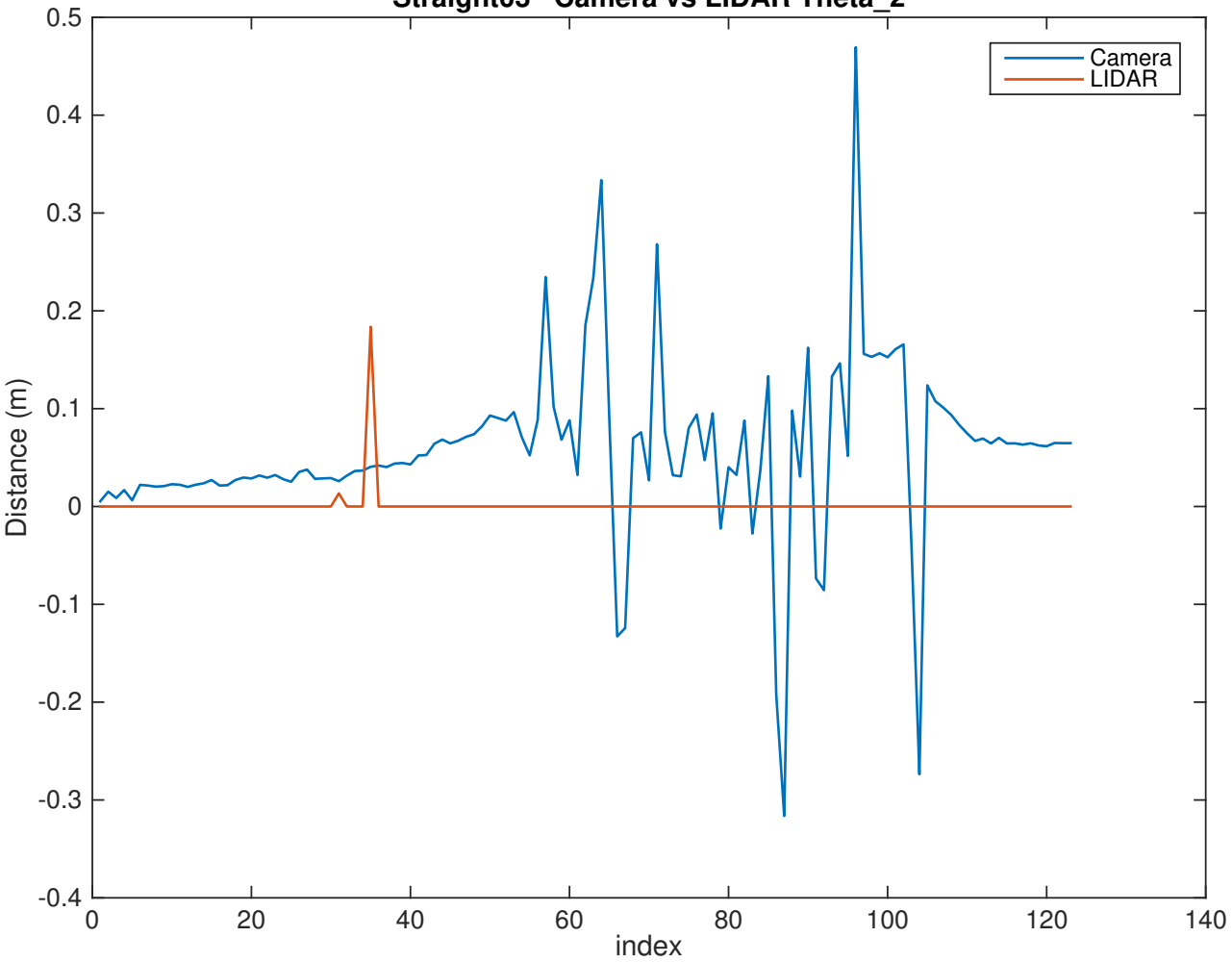
Straight03 LIDAR Theta_1 vs Theta_2



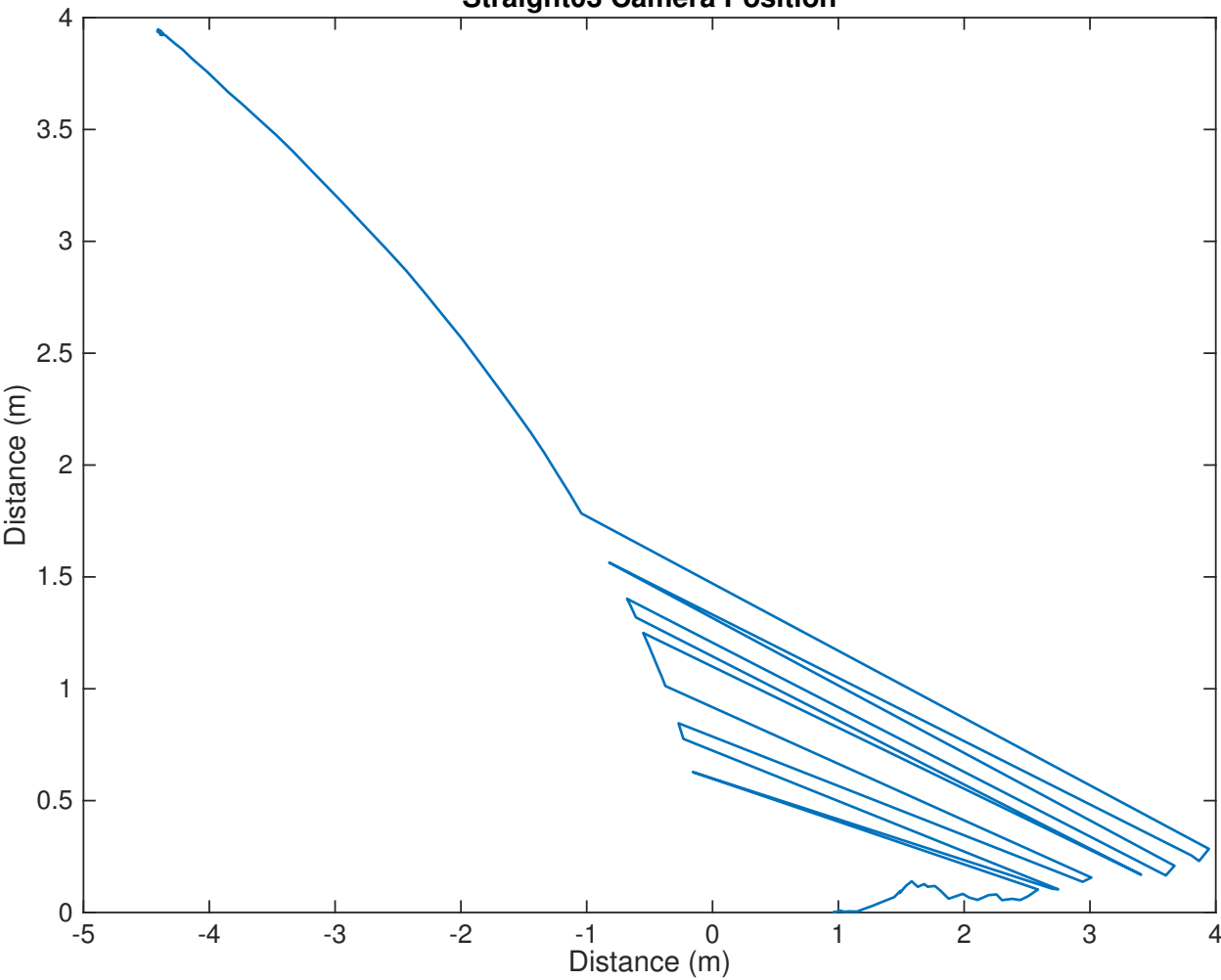
Straight03 Camera vs LIDAR Theta_1



Straight03 Camera vs LIDAR Theta_2

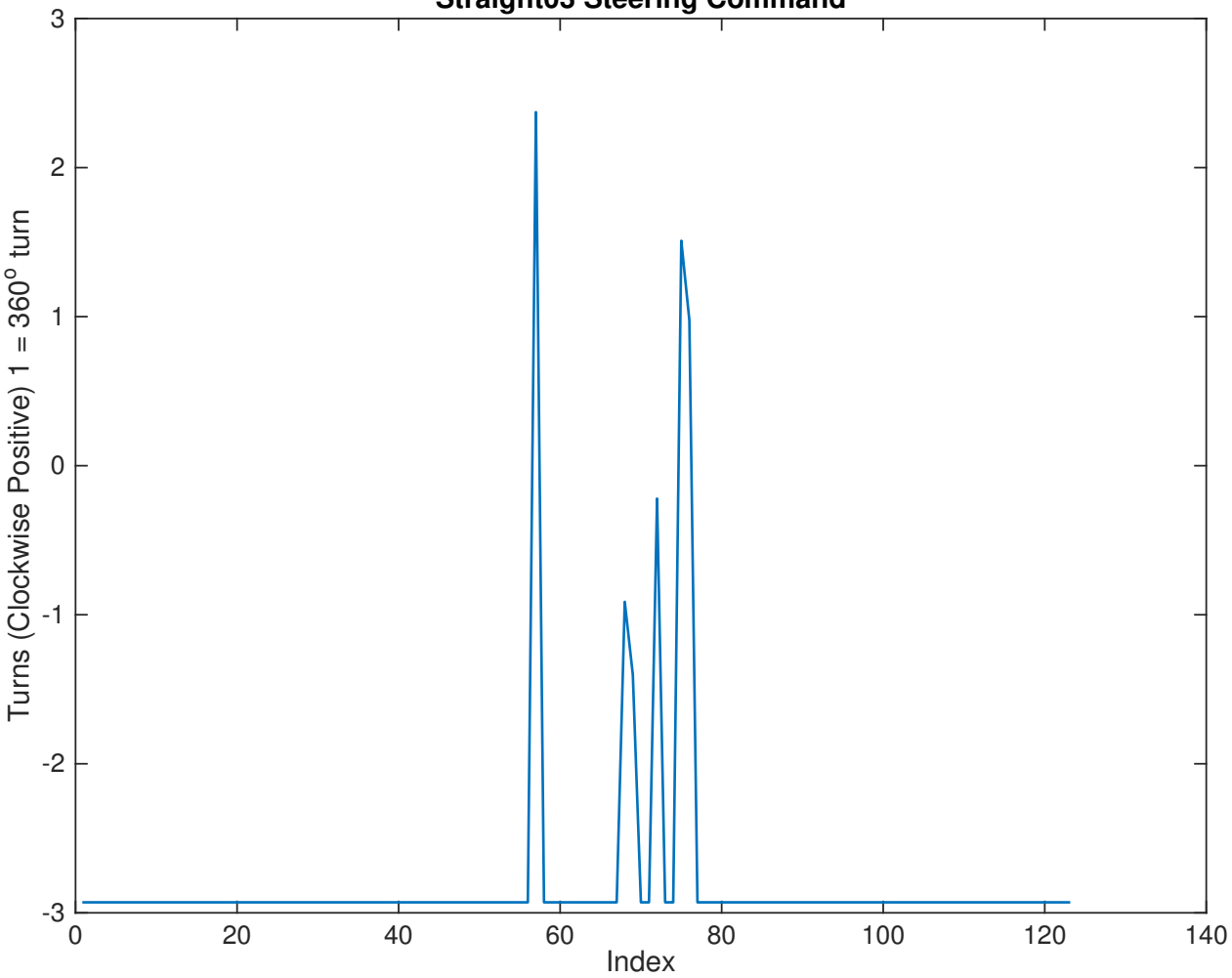


Straight03 Camera Position

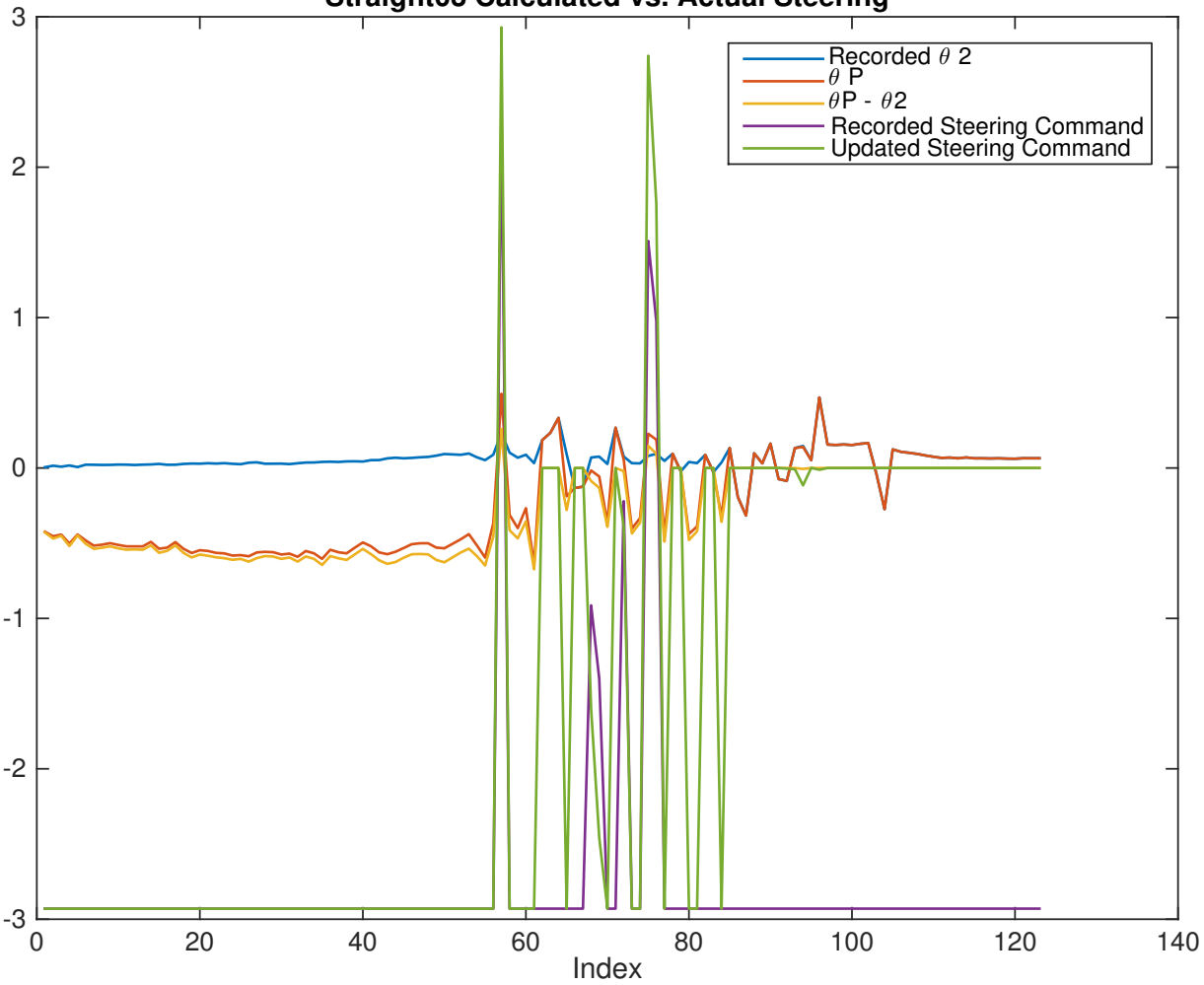


Straight03 Steering Command

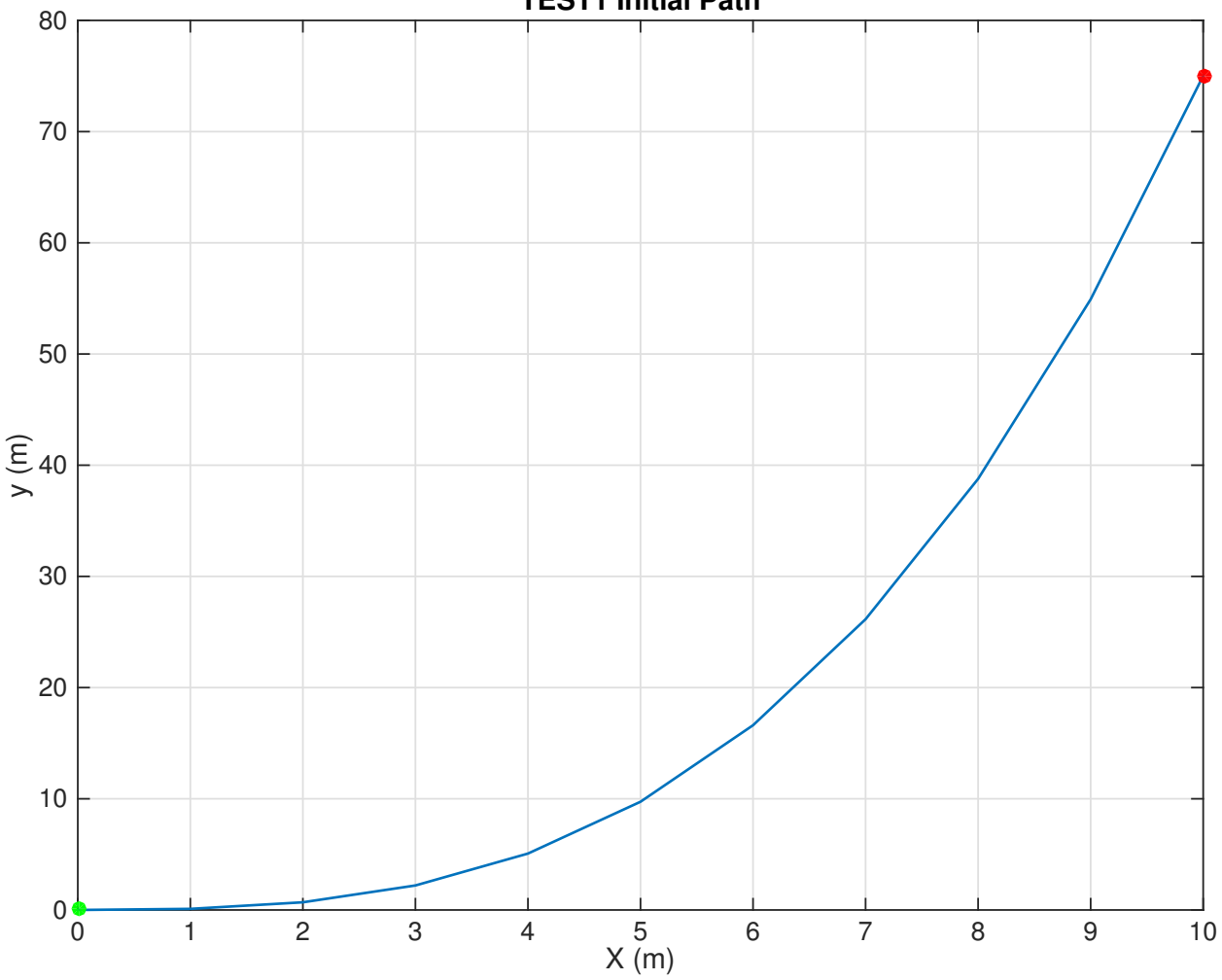
Turns (Clockwise Positive) 1 = 360° turn



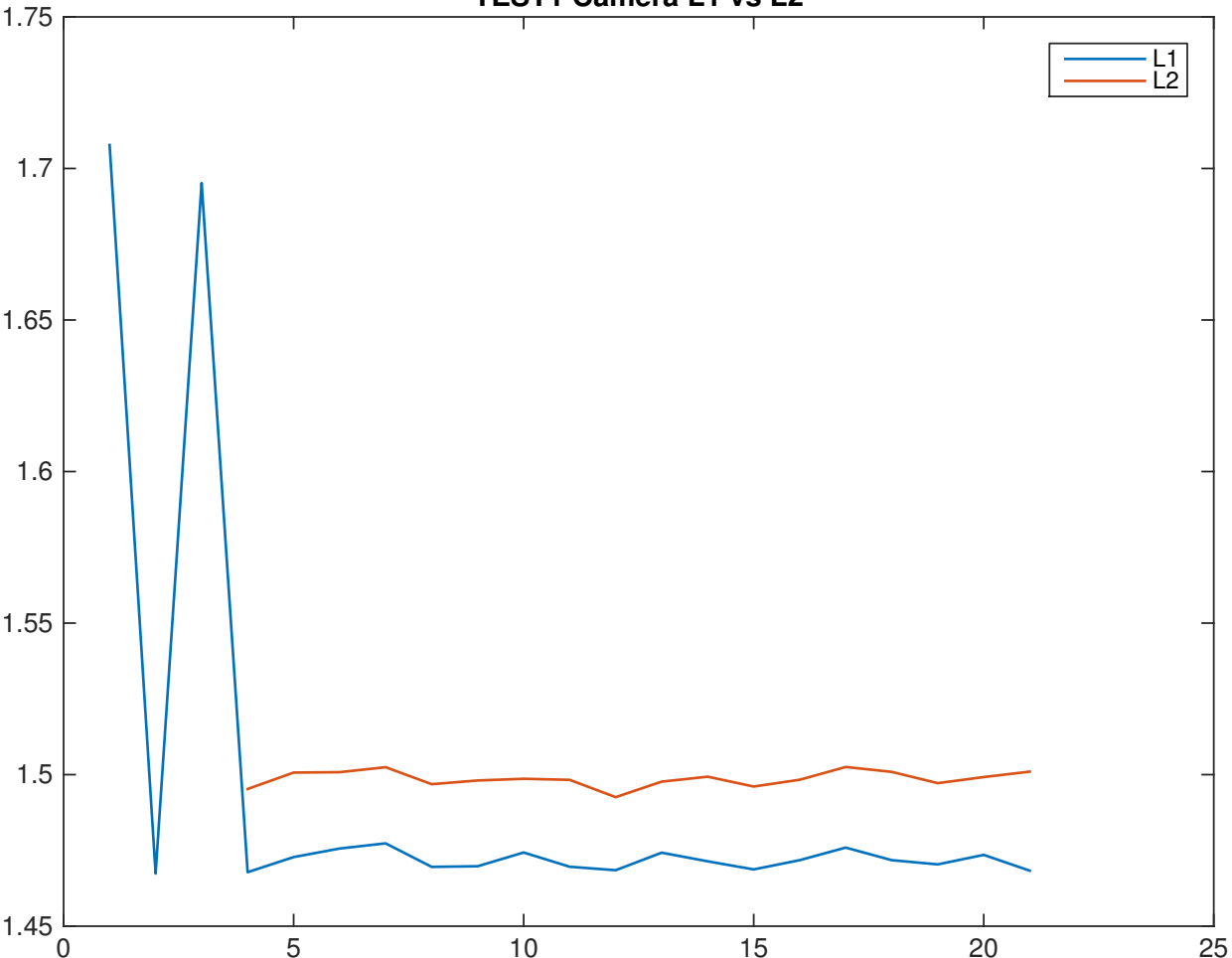
Straight03 Calculated vs. Actual Steering



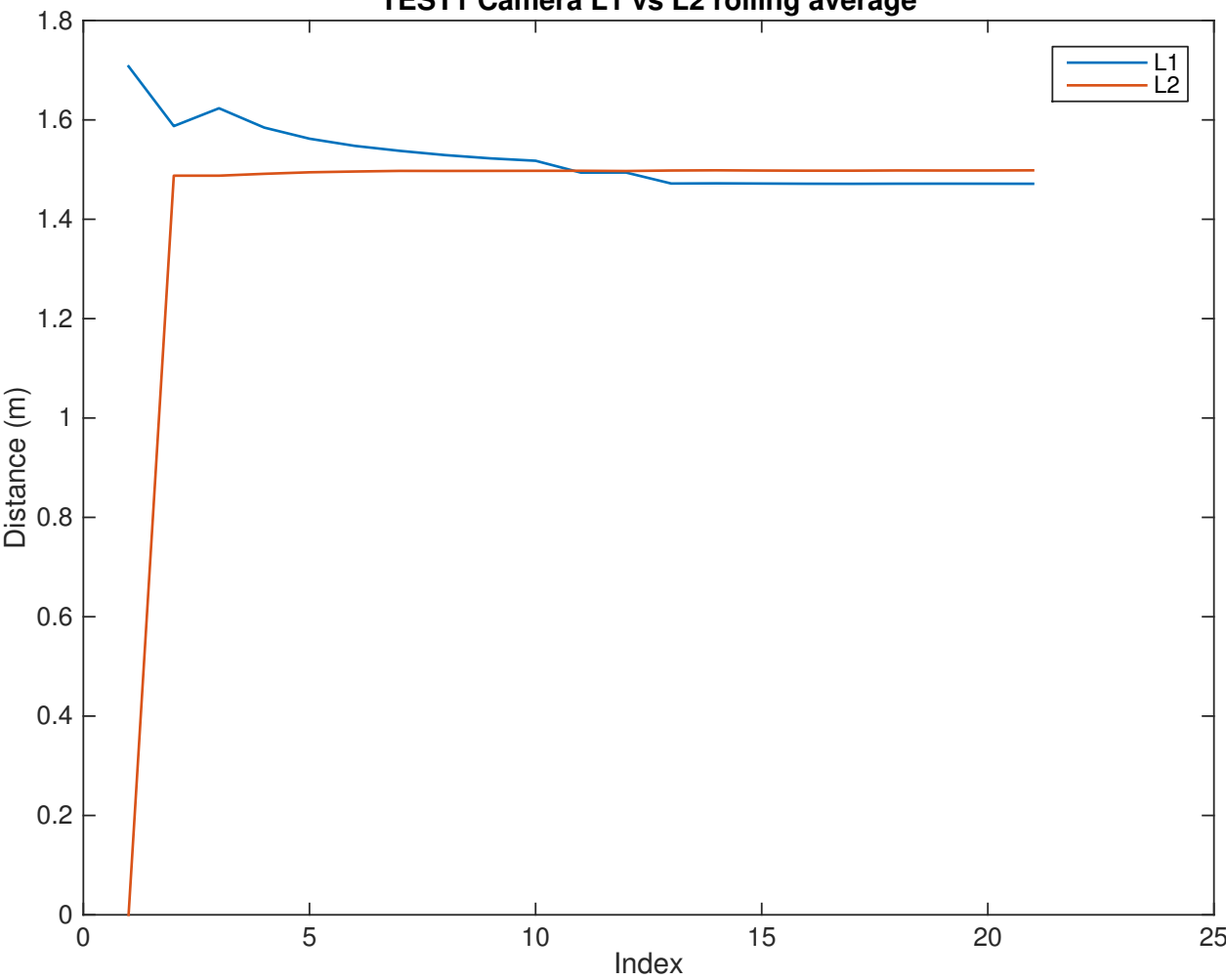
TEST1 Initial Path



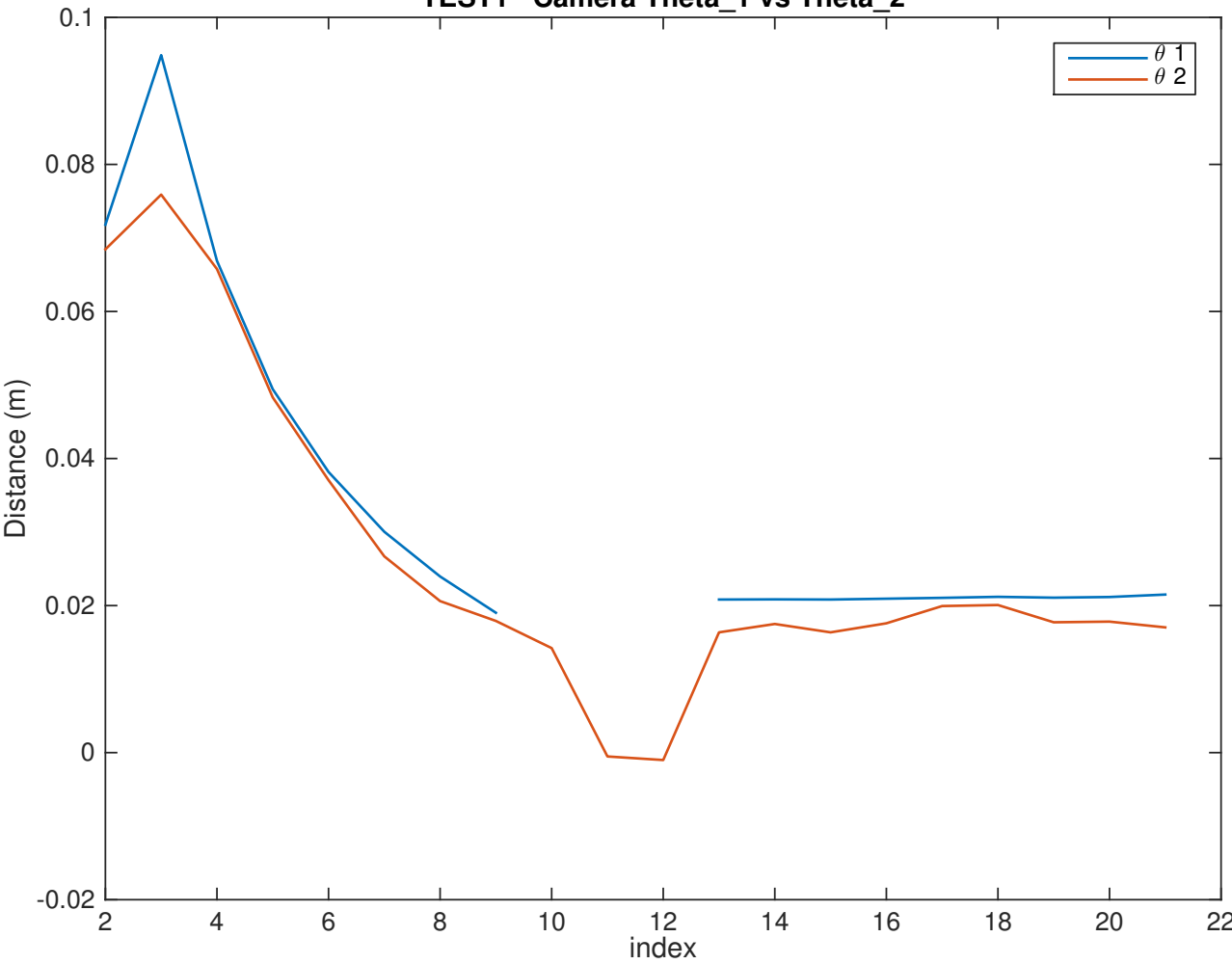
TEST1 Camera L1 vs L2



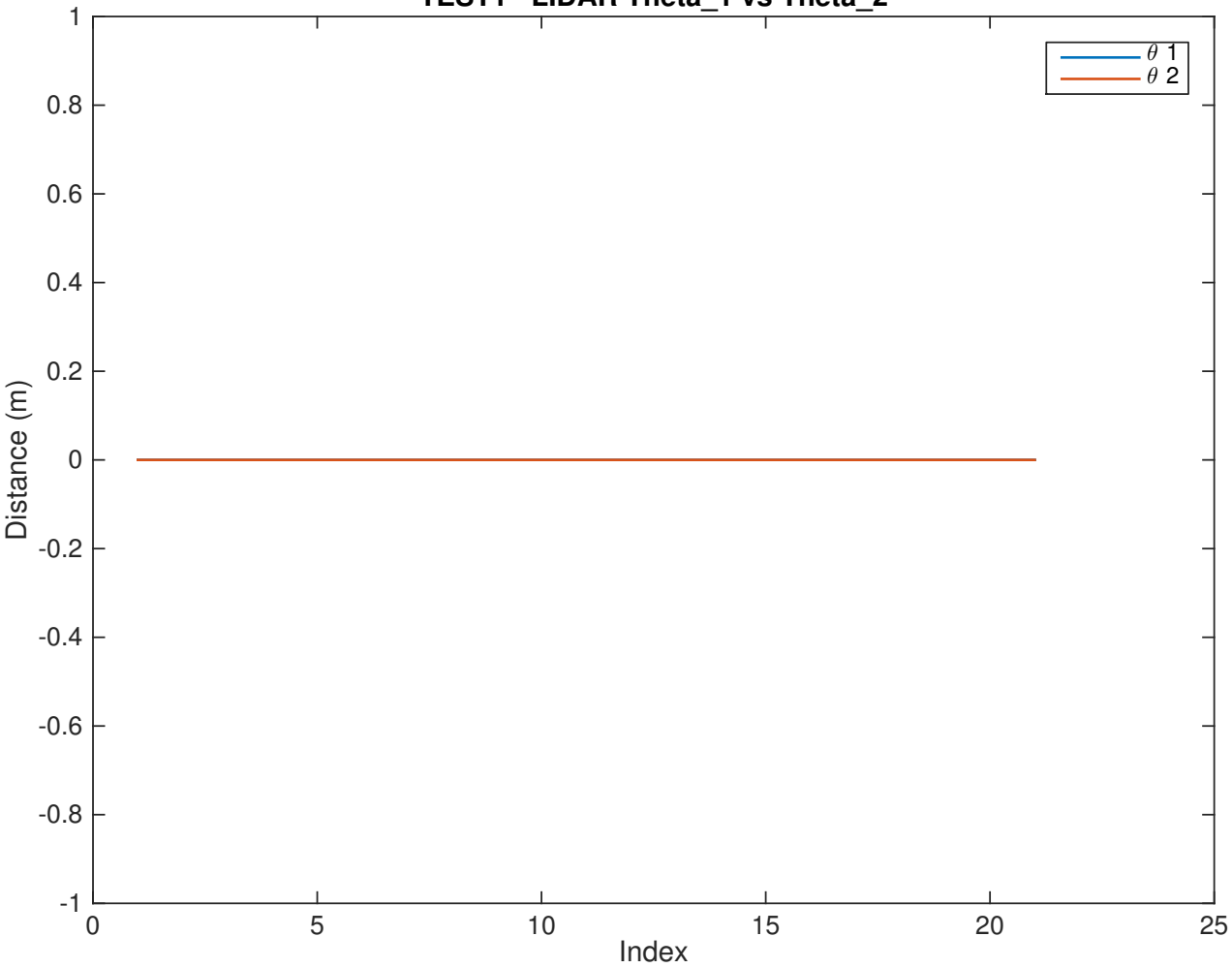
TEST1 Camera L1 vs L2 rolling average



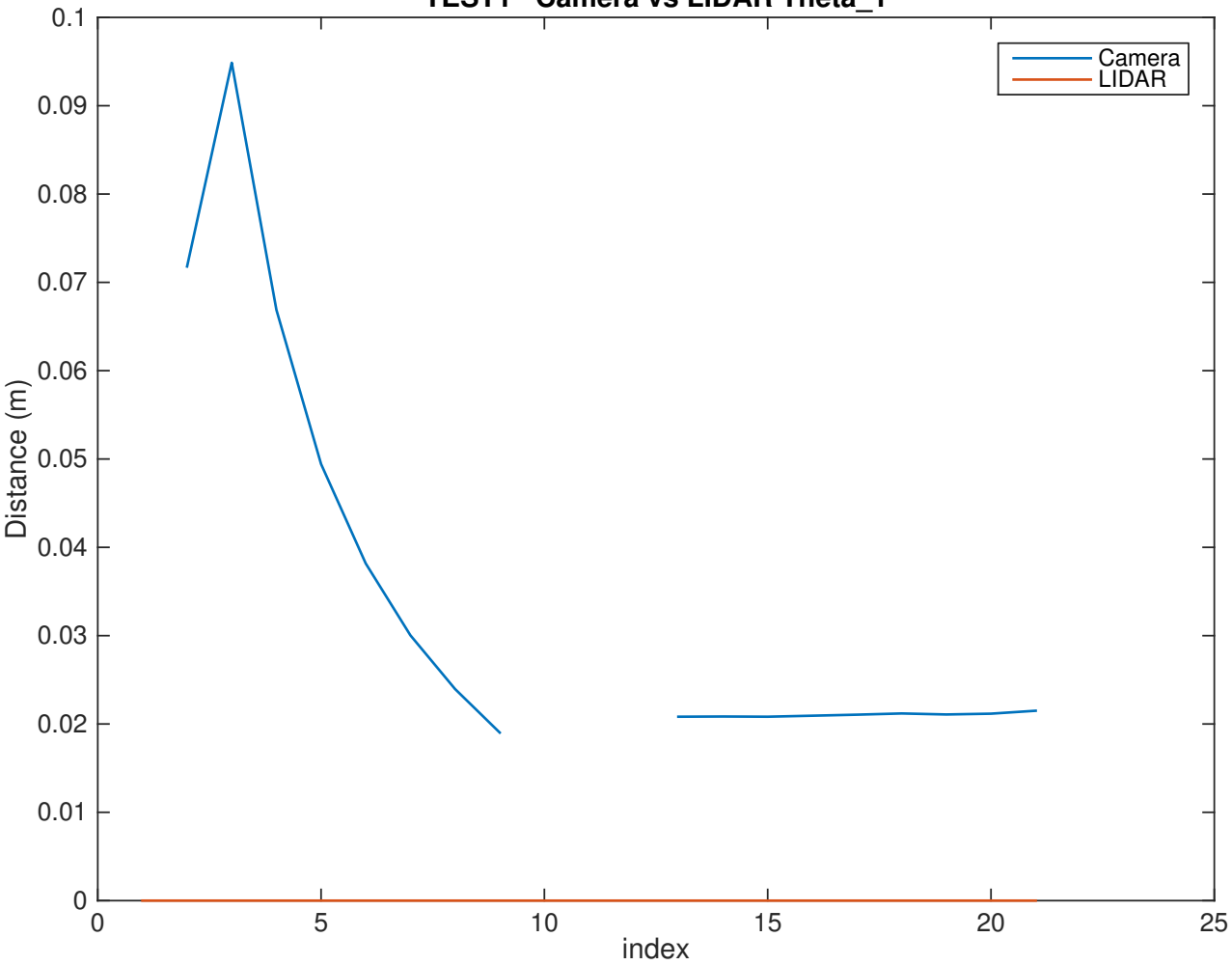
TEST1 Camera Theta_1 vs Theta_2



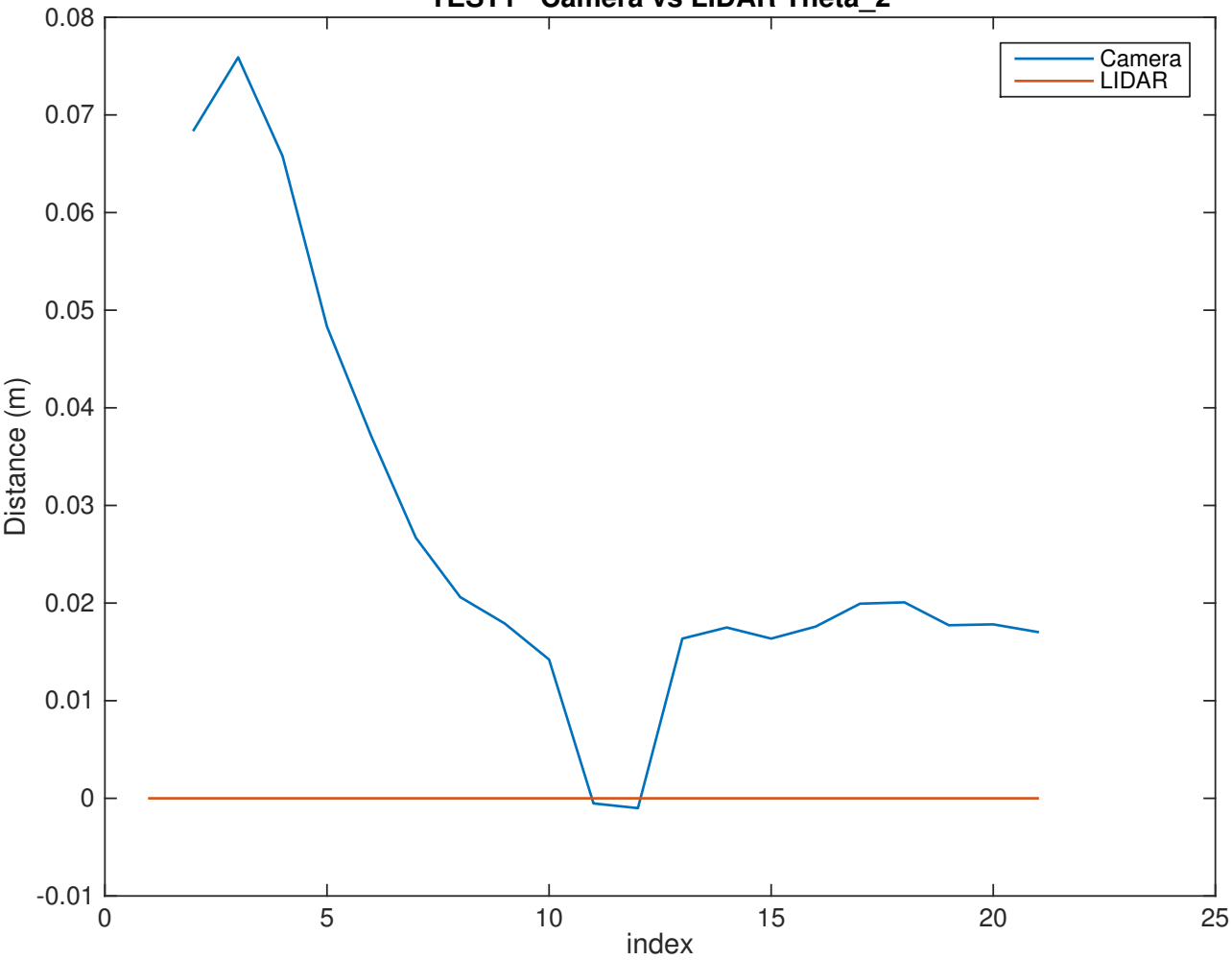
TEST1 LIDAR Theta_1 vs Theta_2



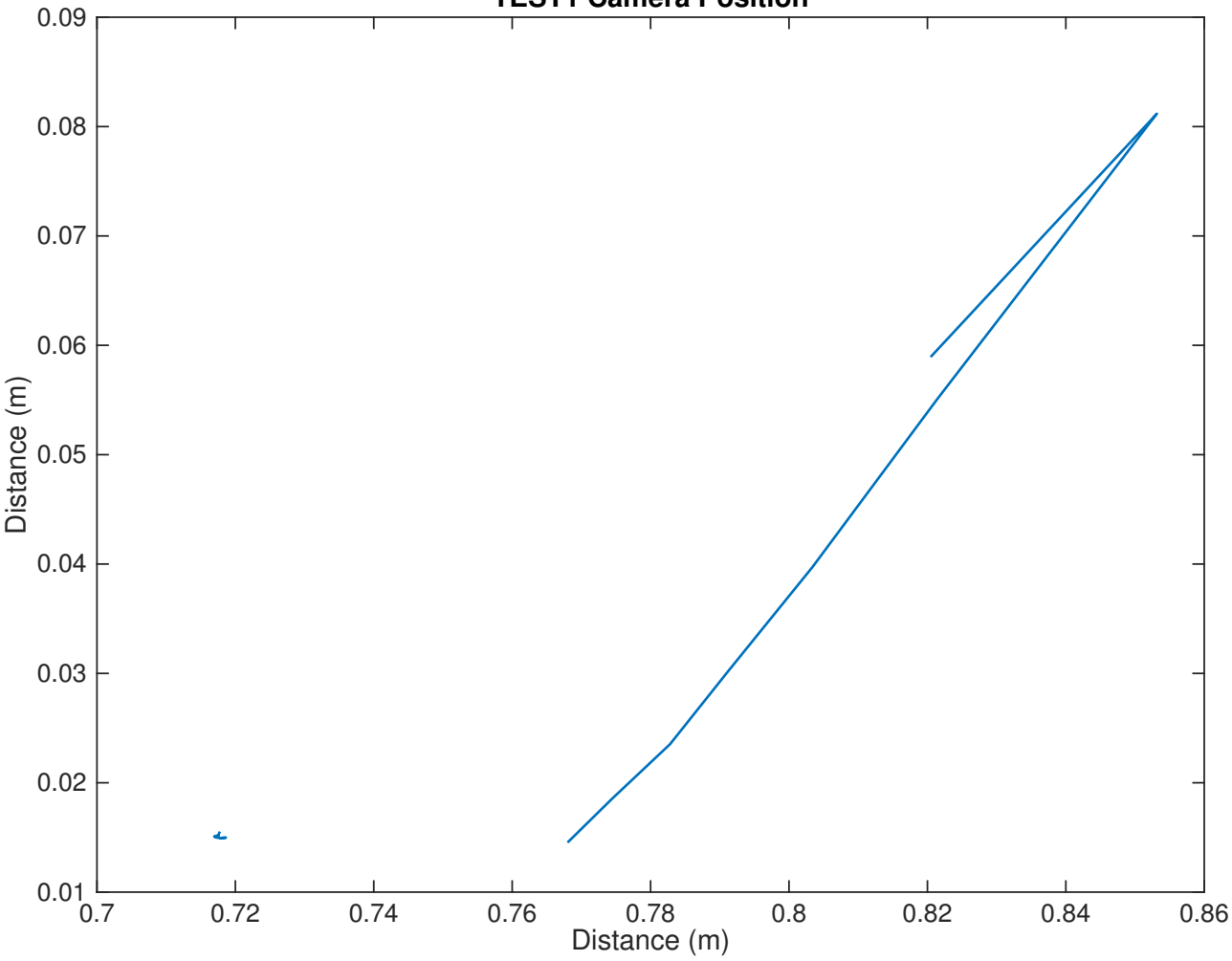
TEST1 Camera vs LIDAR Theta_1



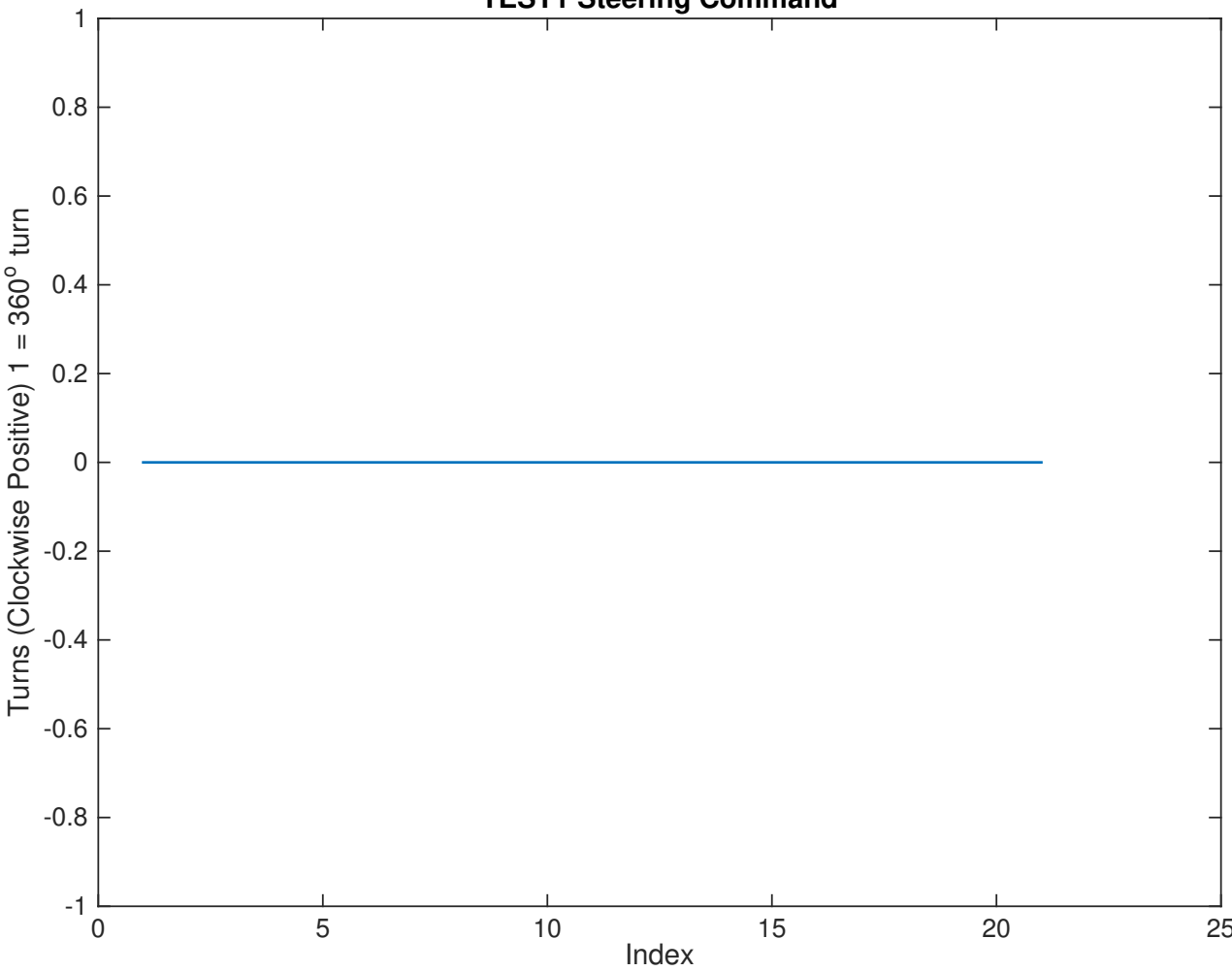
TEST1 Camera vs LIDAR Theta_2



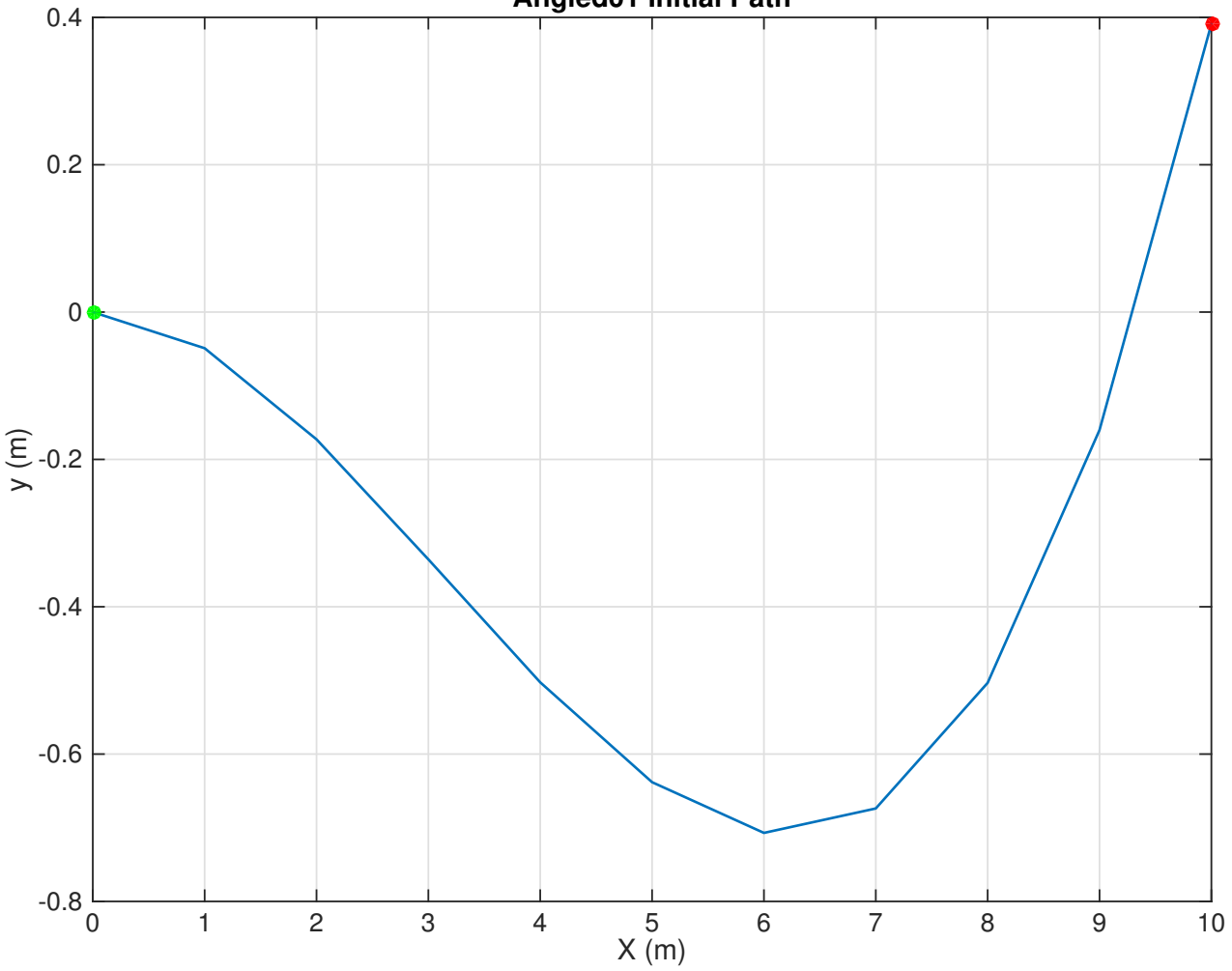
TEST1 Camera Position



TEST1 Steering Command



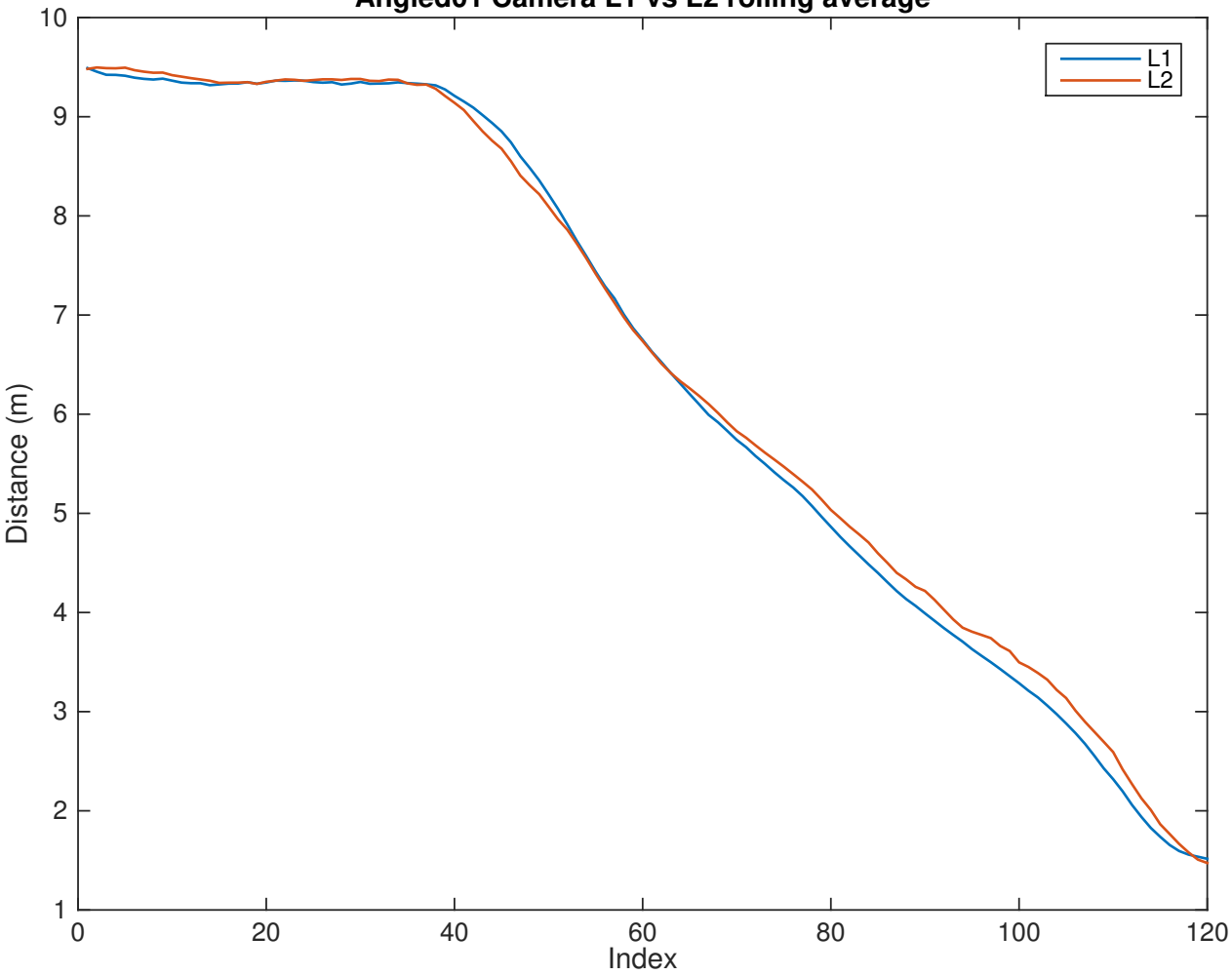
Angled01 Initial Path



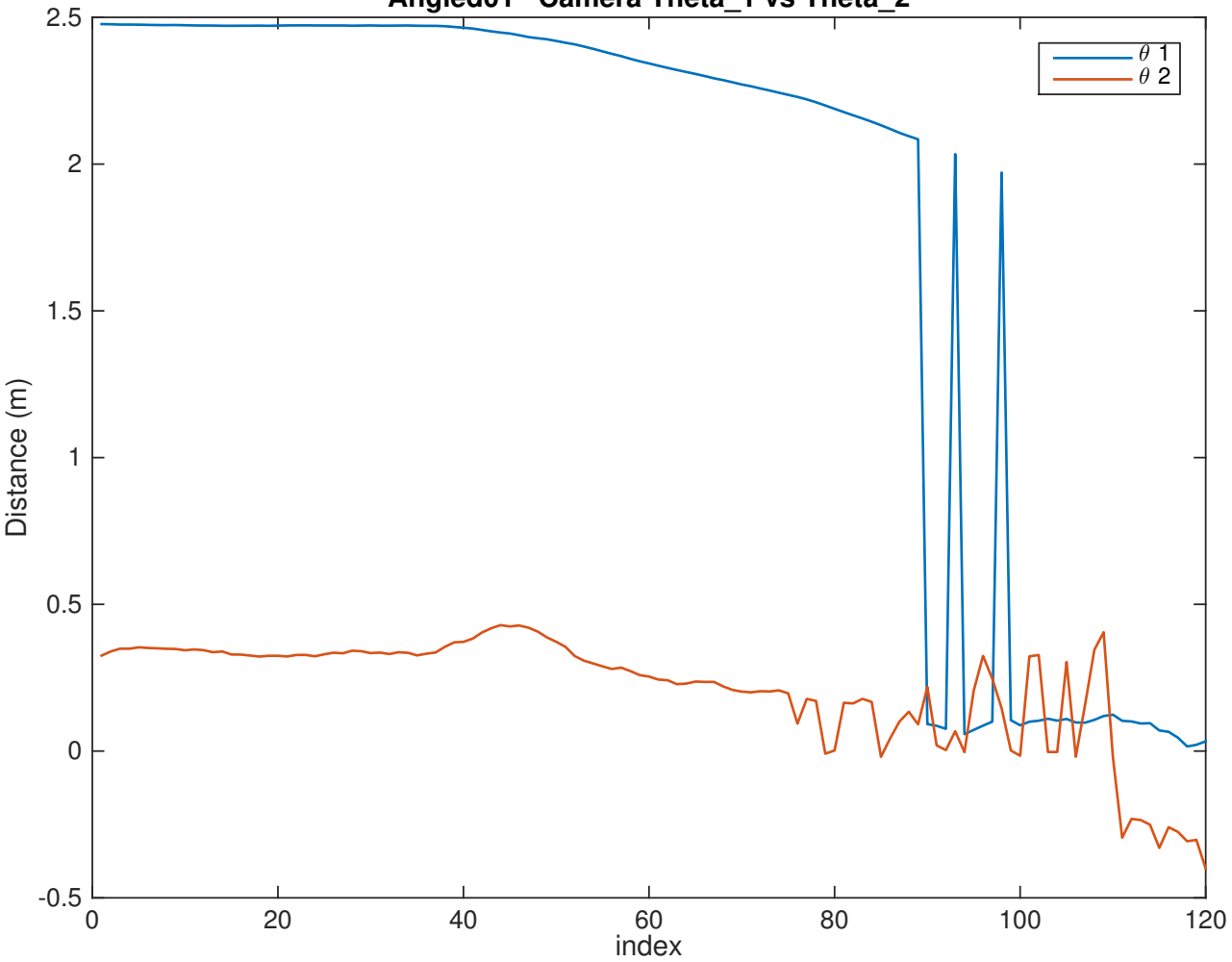
Angled01 Camera L1 vs L2



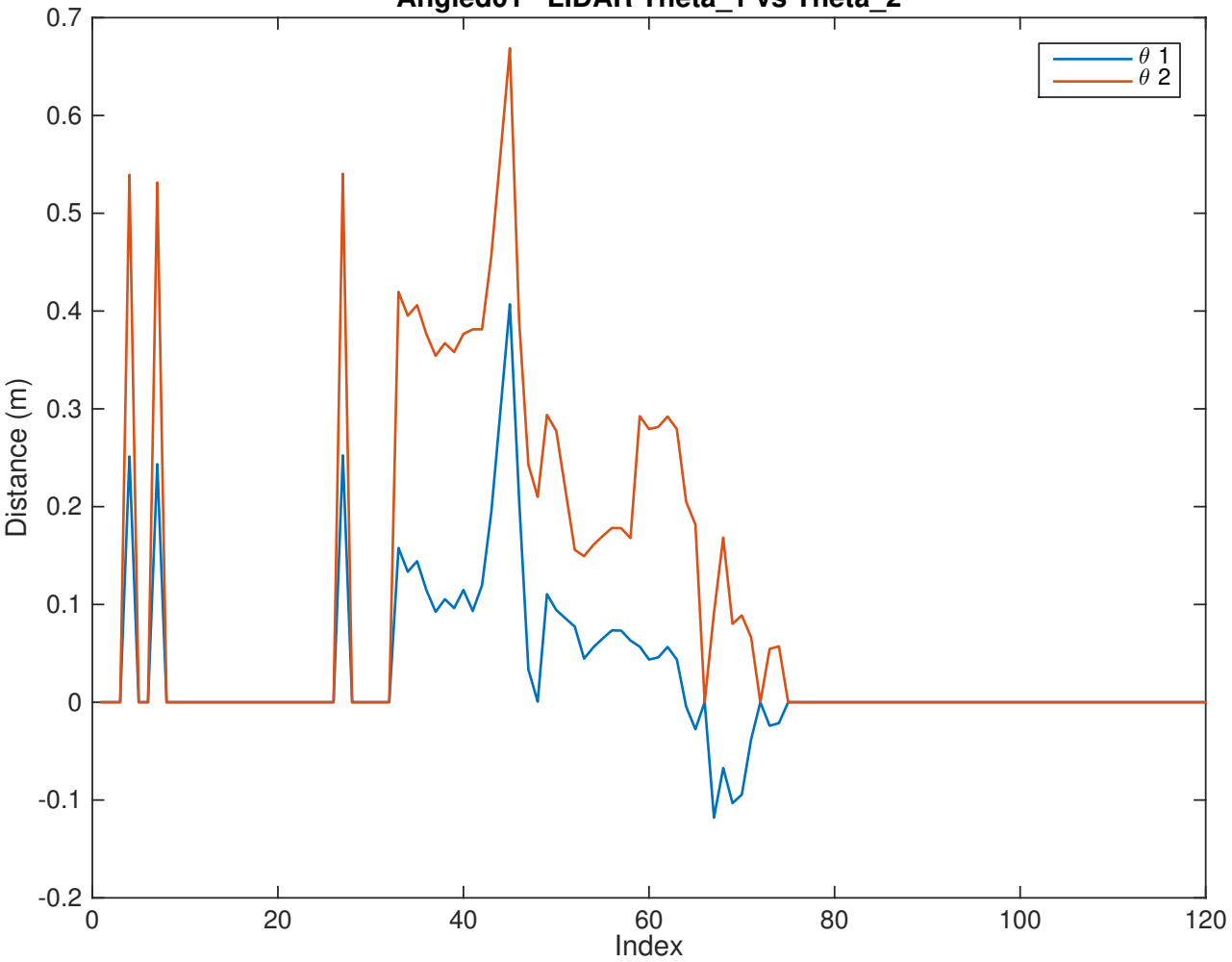
Angled01 Camera L1 vs L2 rolling average



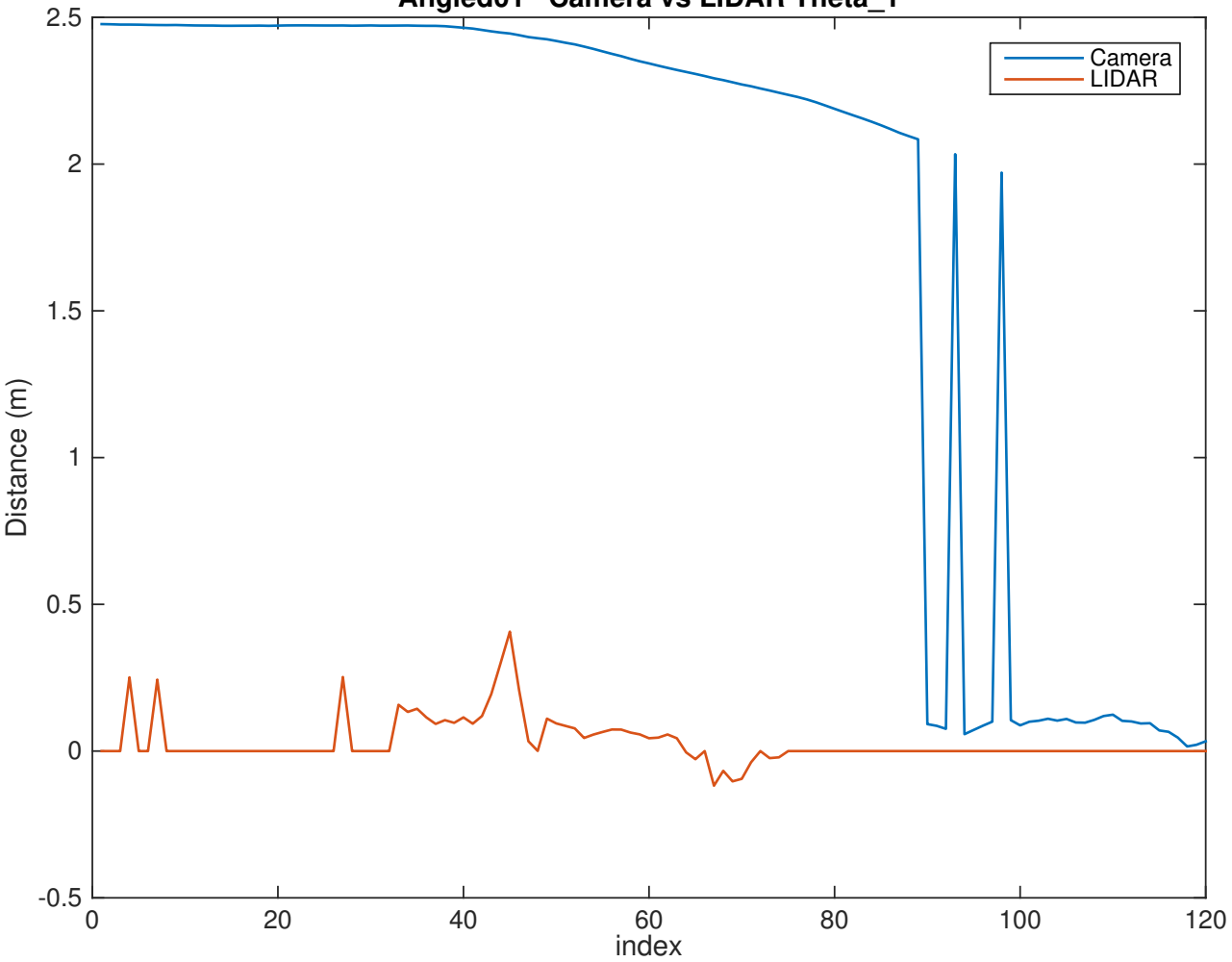
Angled01 Camera Theta_1 vs Theta_2



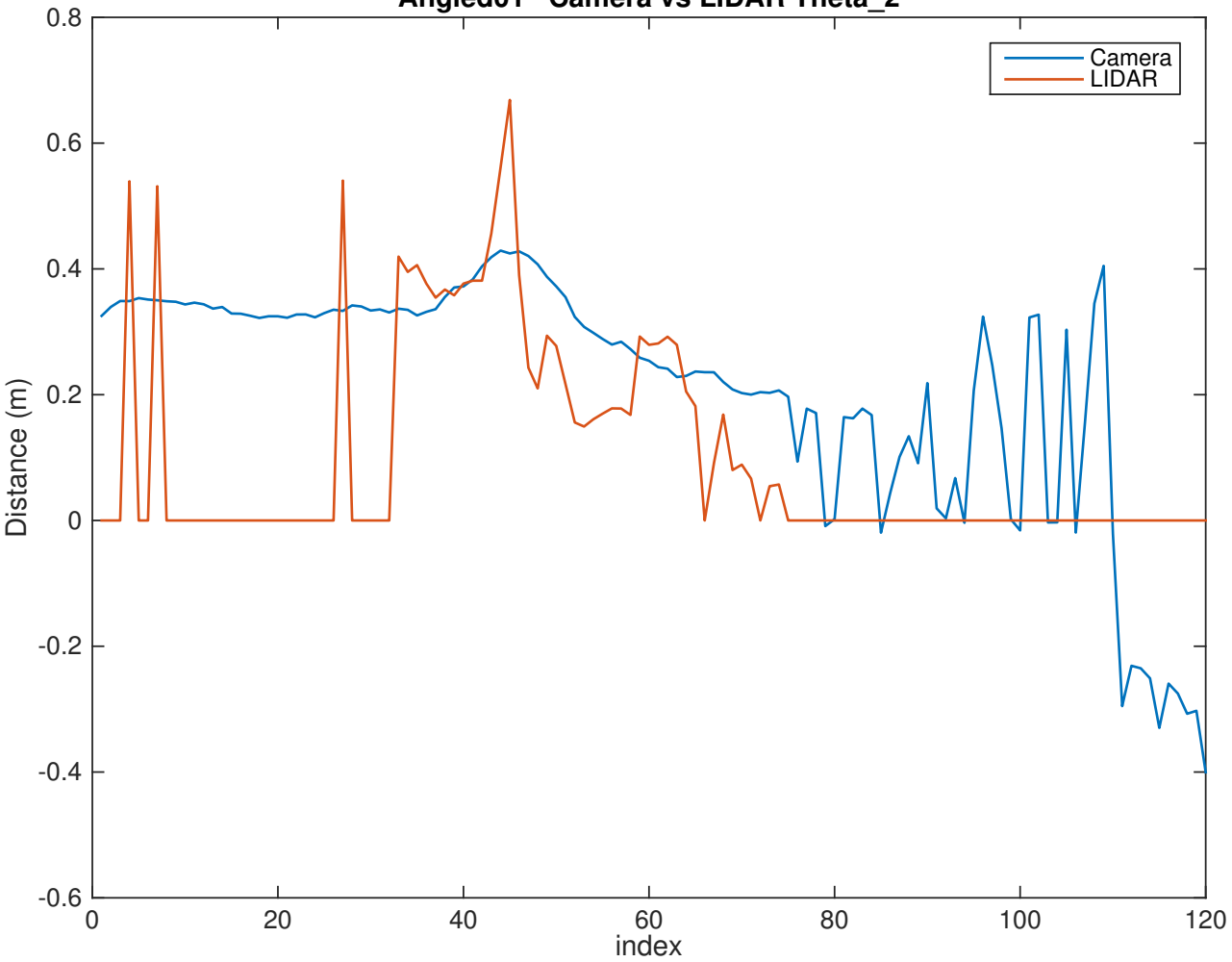
Angled01 LIDAR Theta_1 vs Theta_2



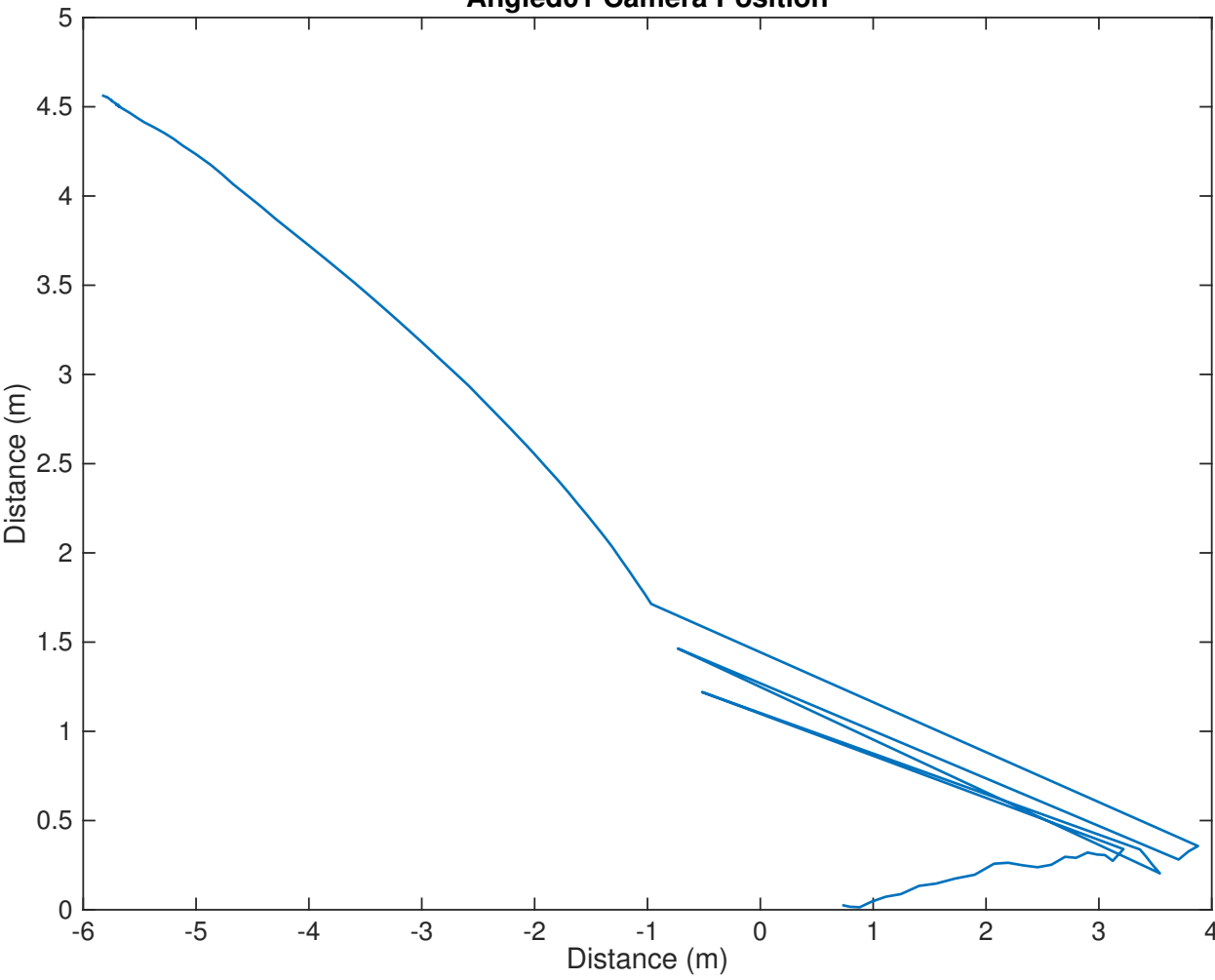
Angled01 Camera vs LIDAR Theta_1



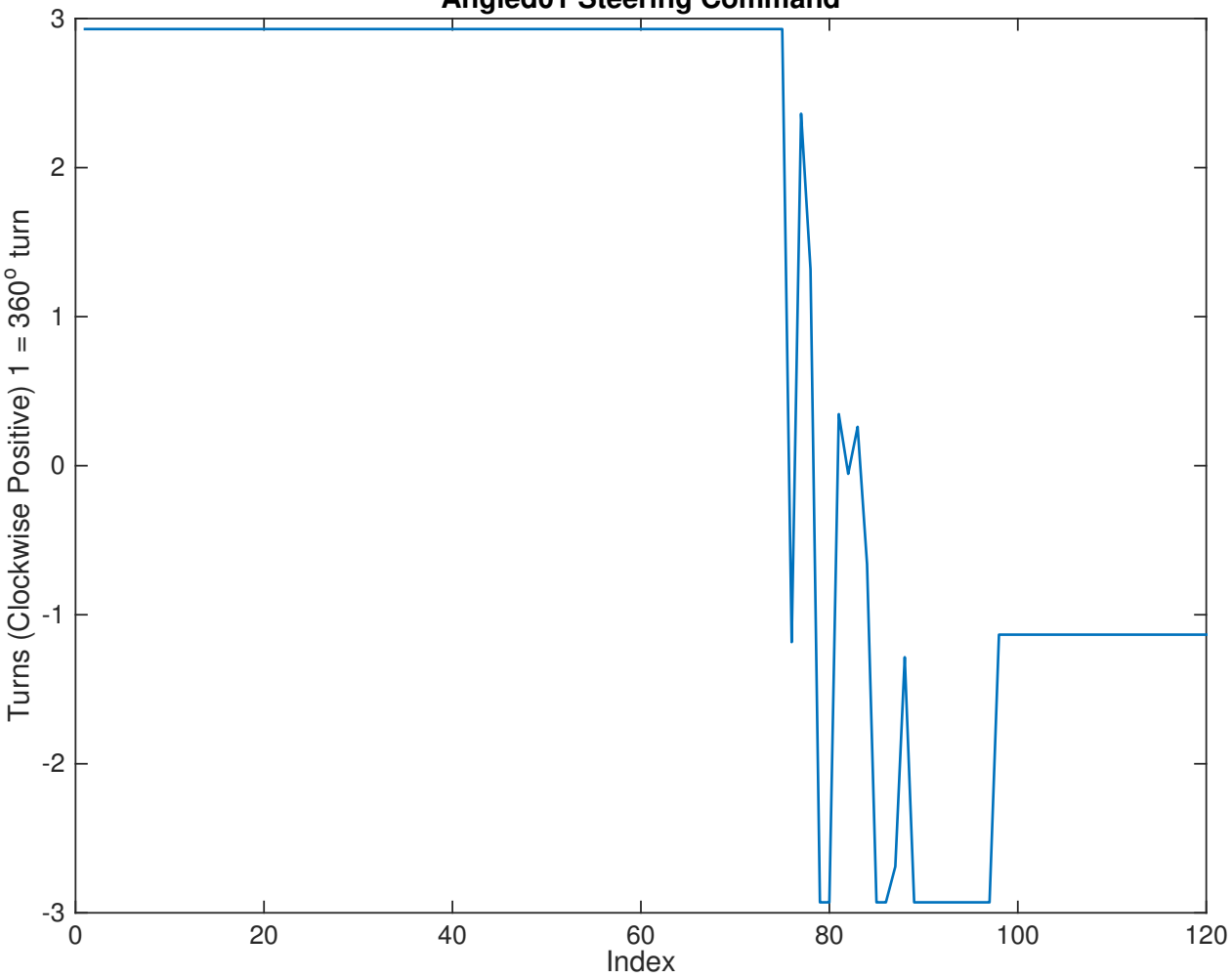
Angled01 Camera vs LIDAR Theta_2



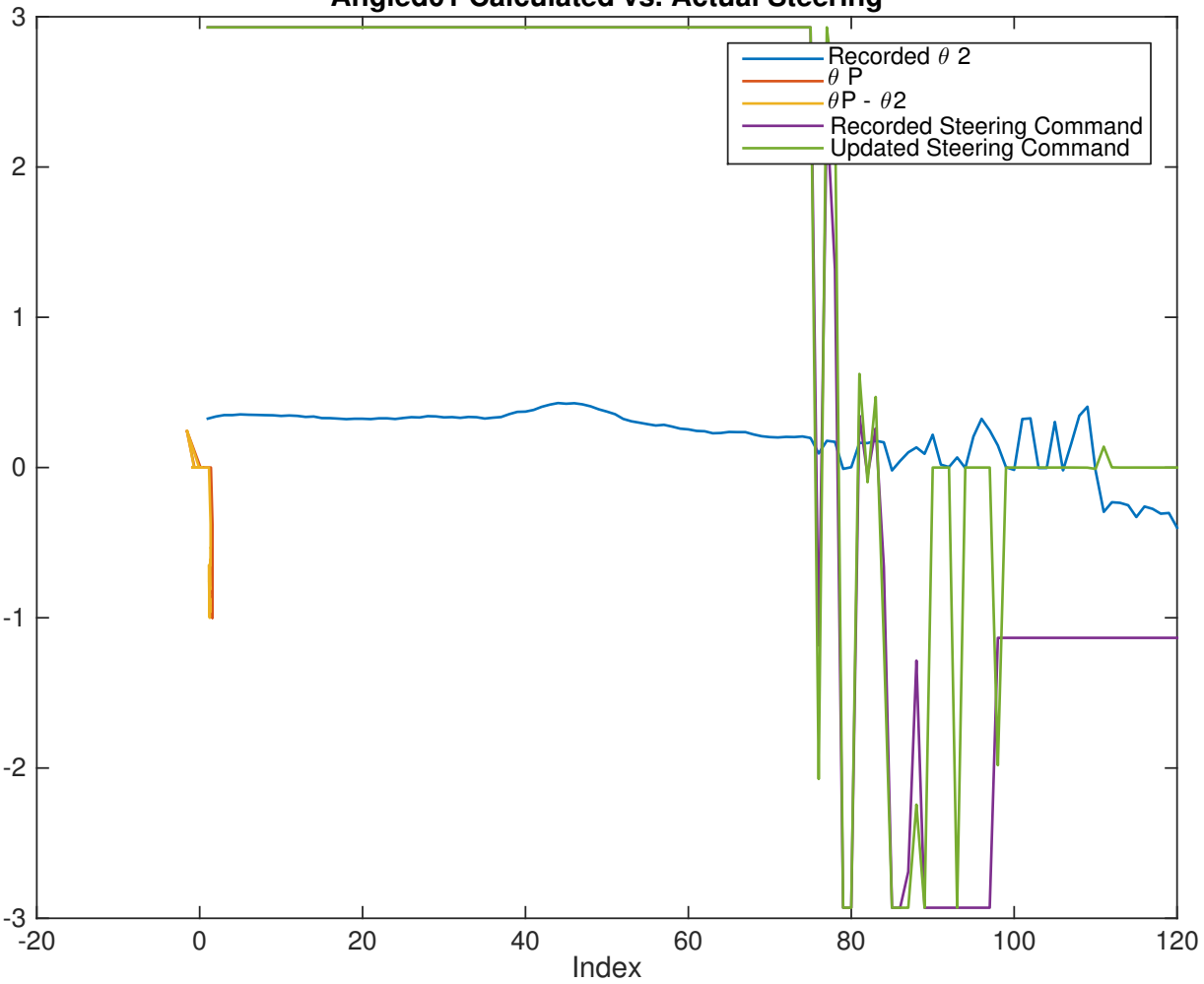
Angled01 Camera Position



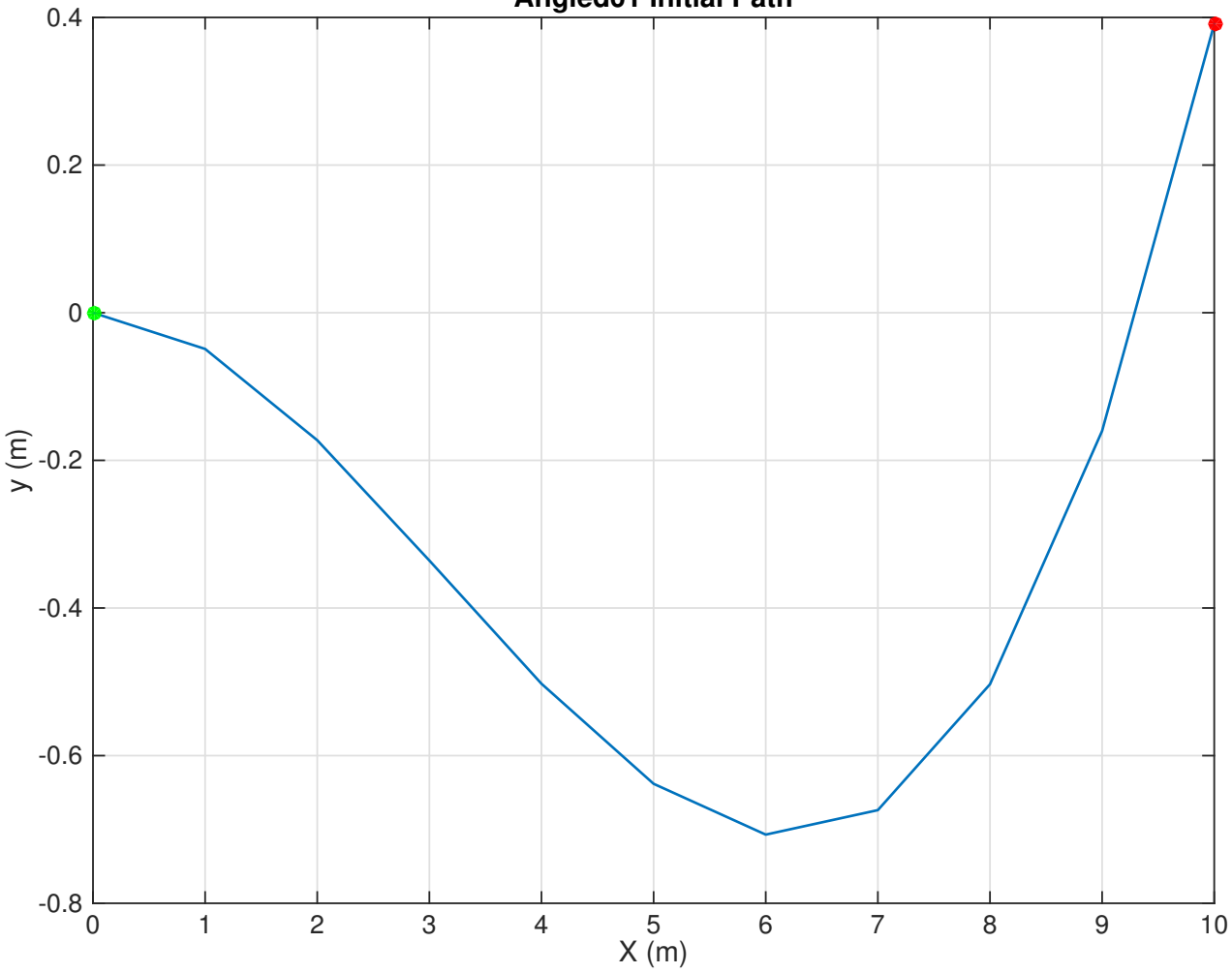
Angled01 Steering Command



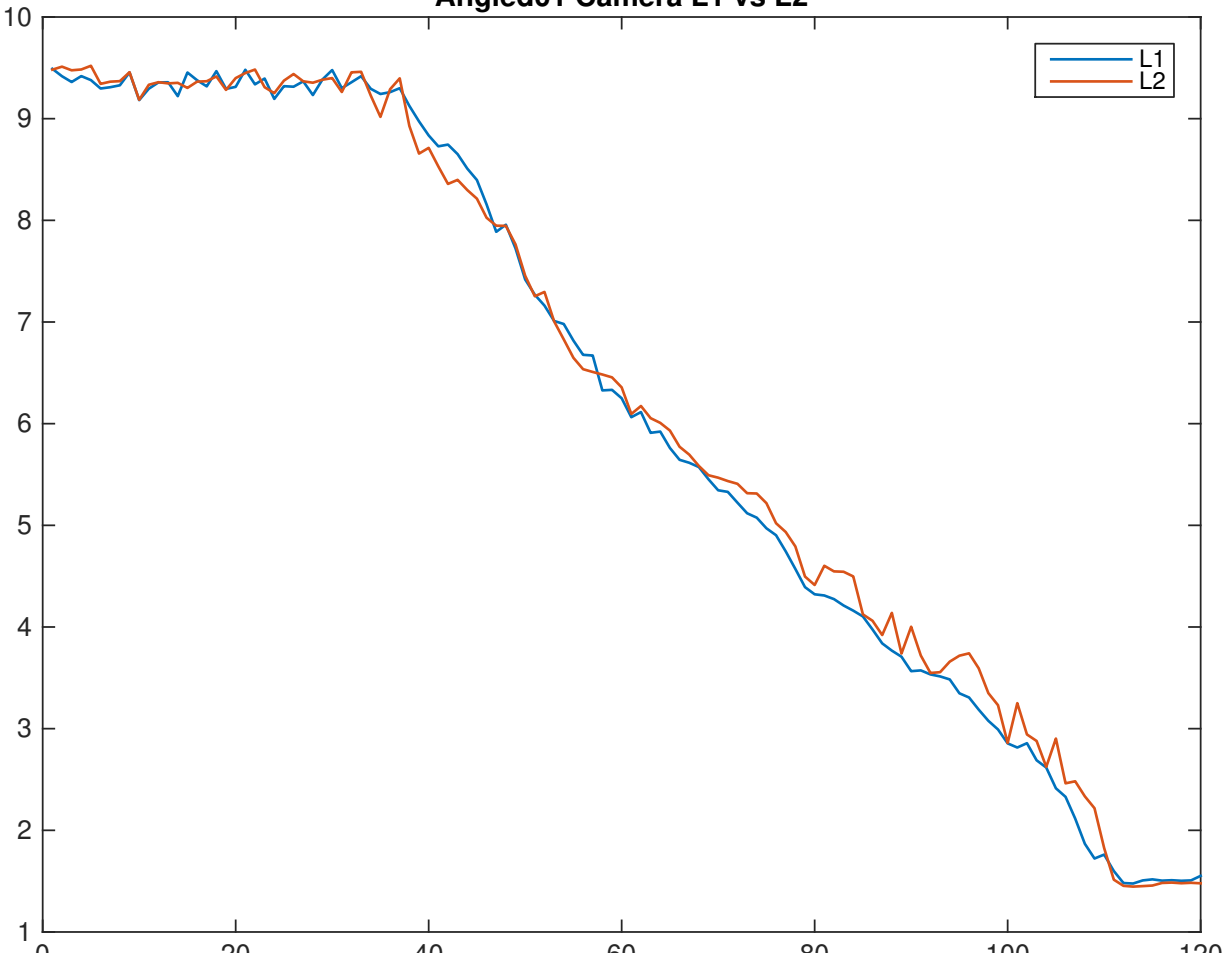
Angled01 Calculated vs. Actual Steering



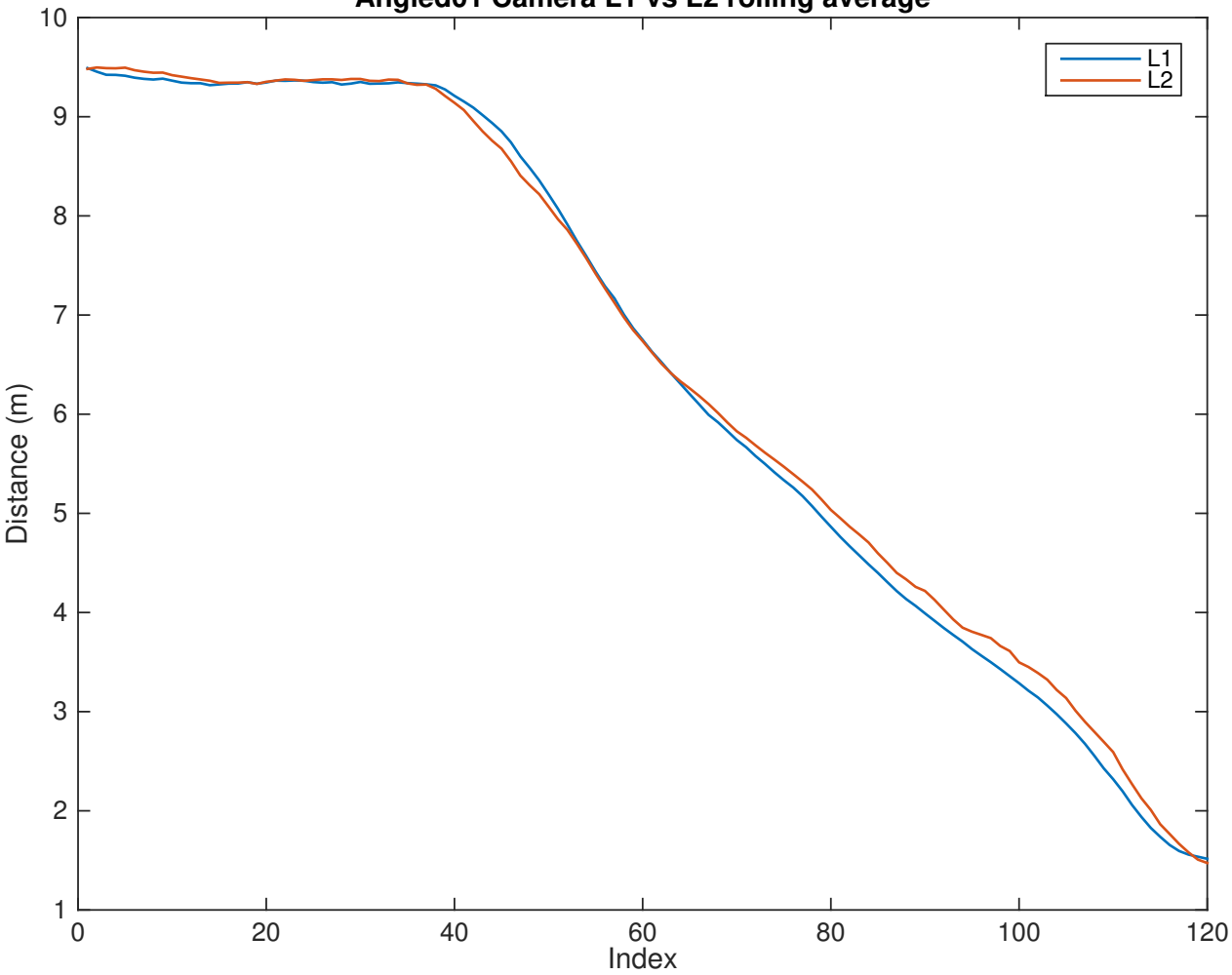
Angled01 Initial Path



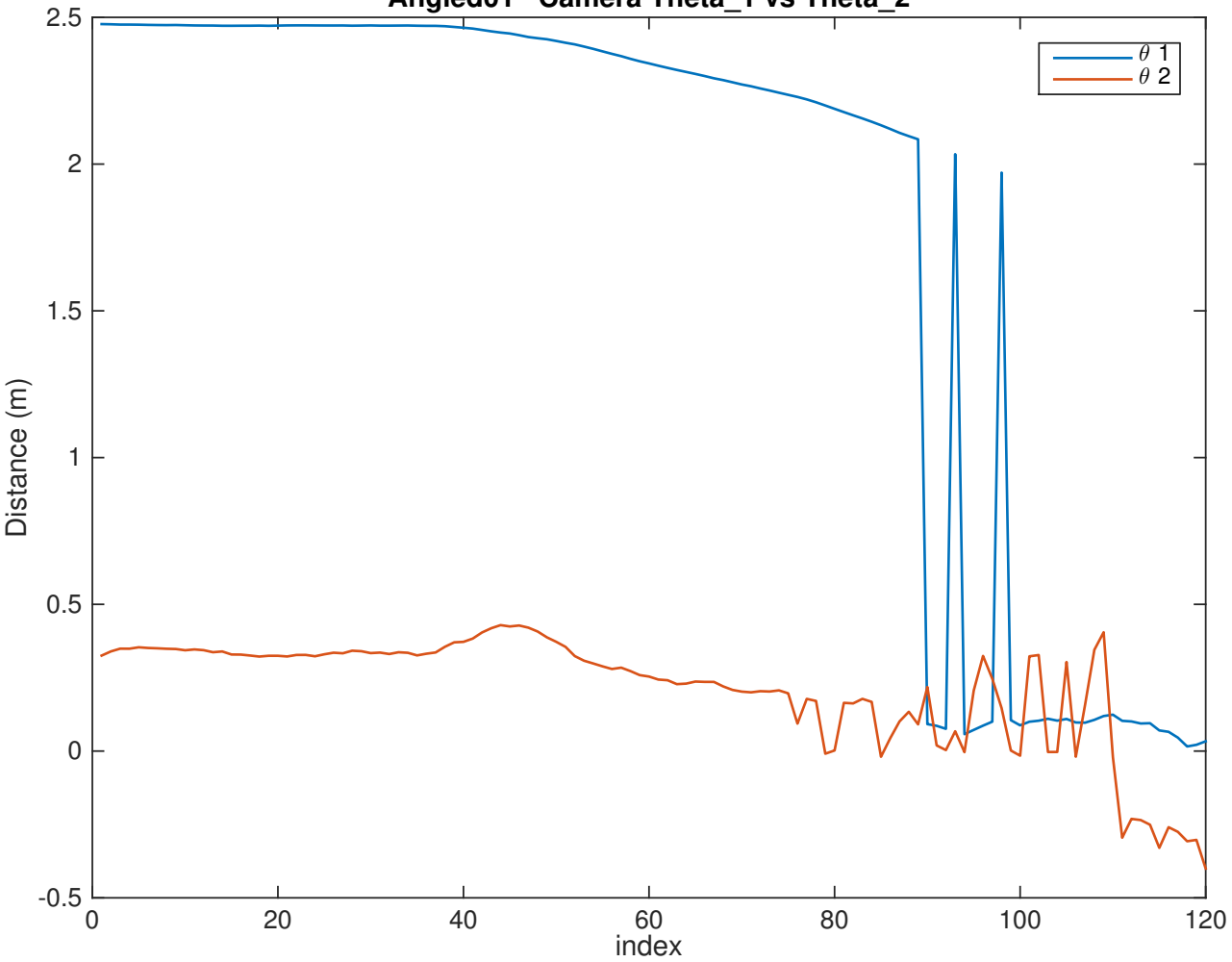
Angled01 Camera L1 vs L2



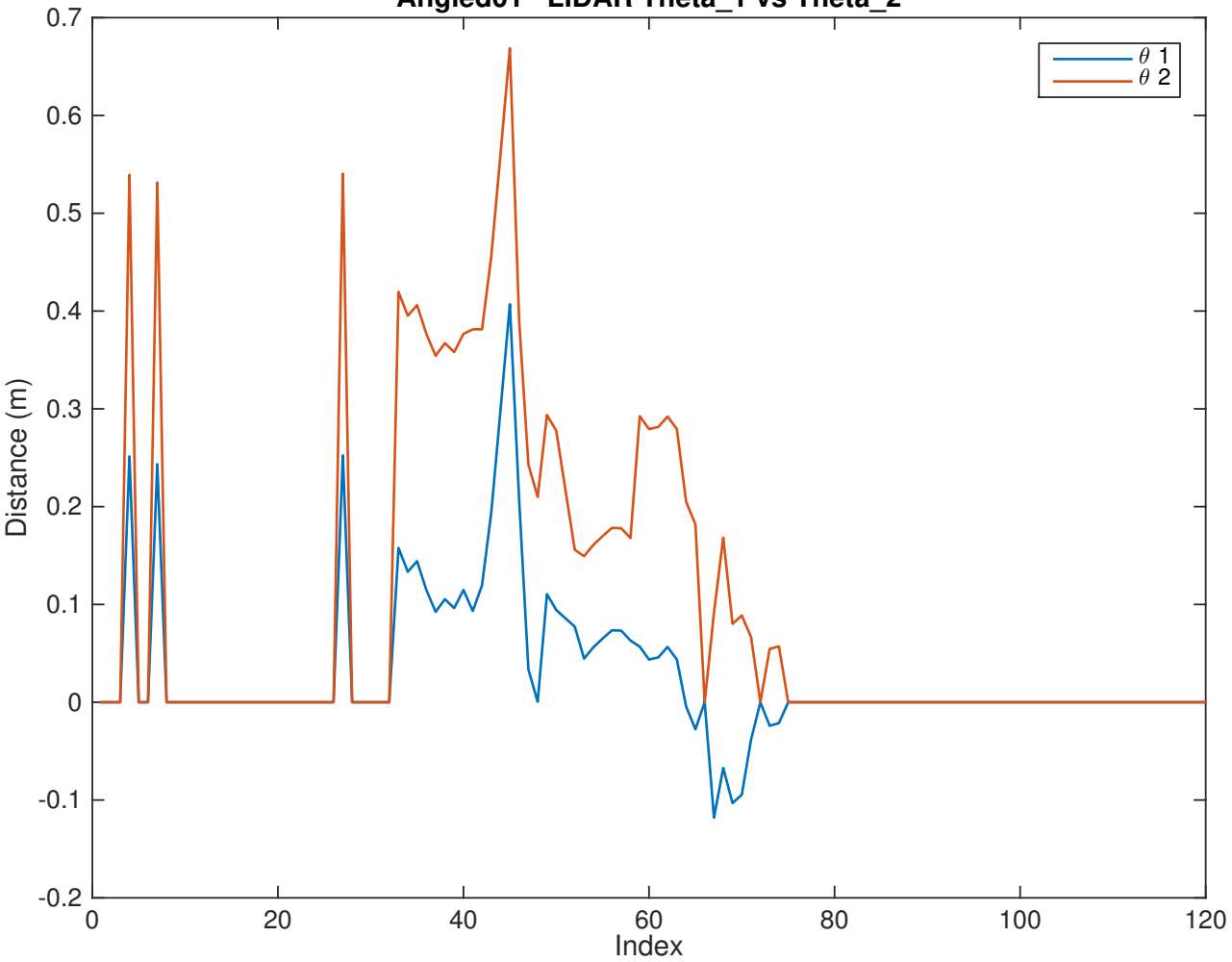
Angled01 Camera L1 vs L2 rolling average



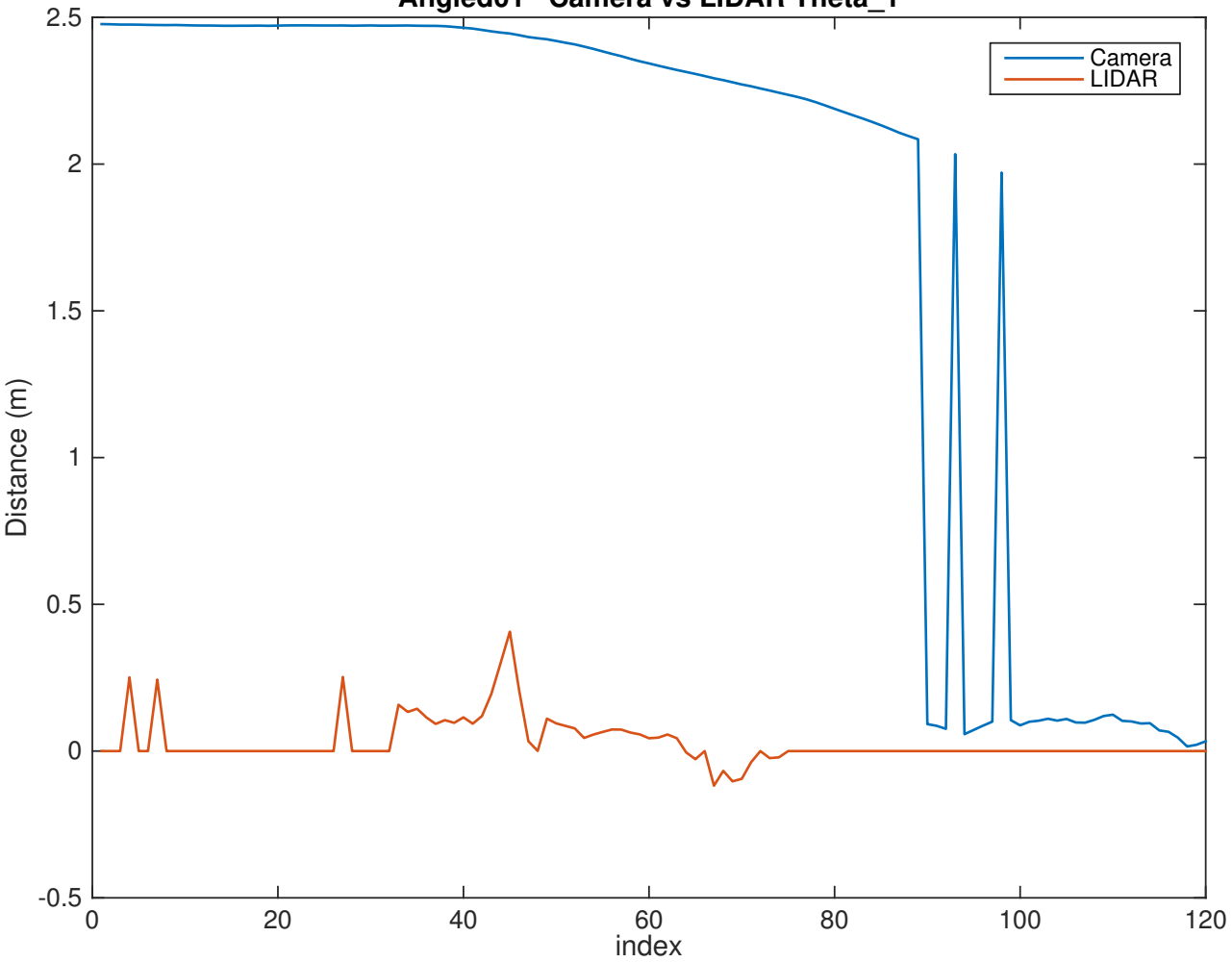
Angled01 Camera Theta_1 vs Theta_2



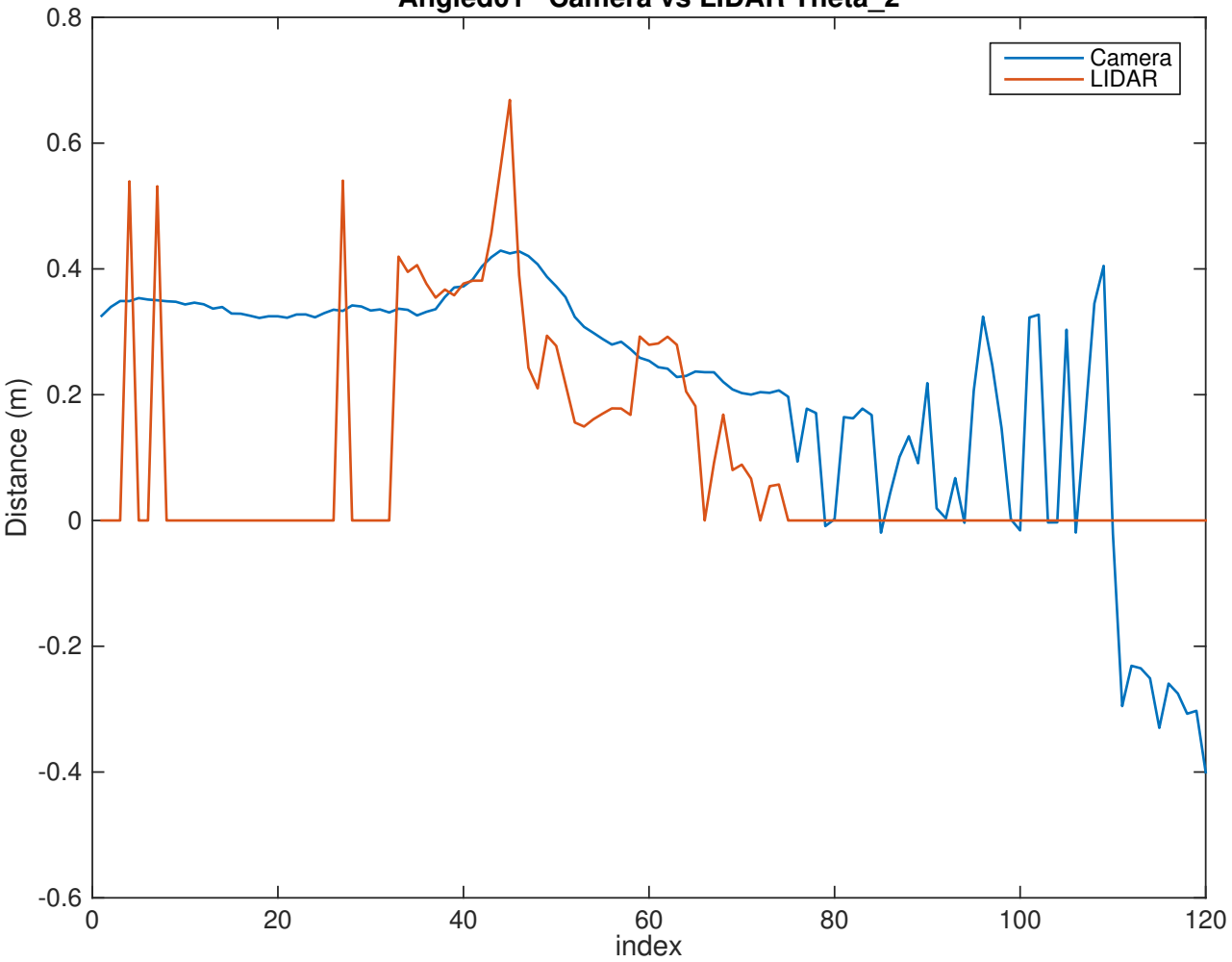
Angled01 LIDAR Theta_1 vs Theta_2



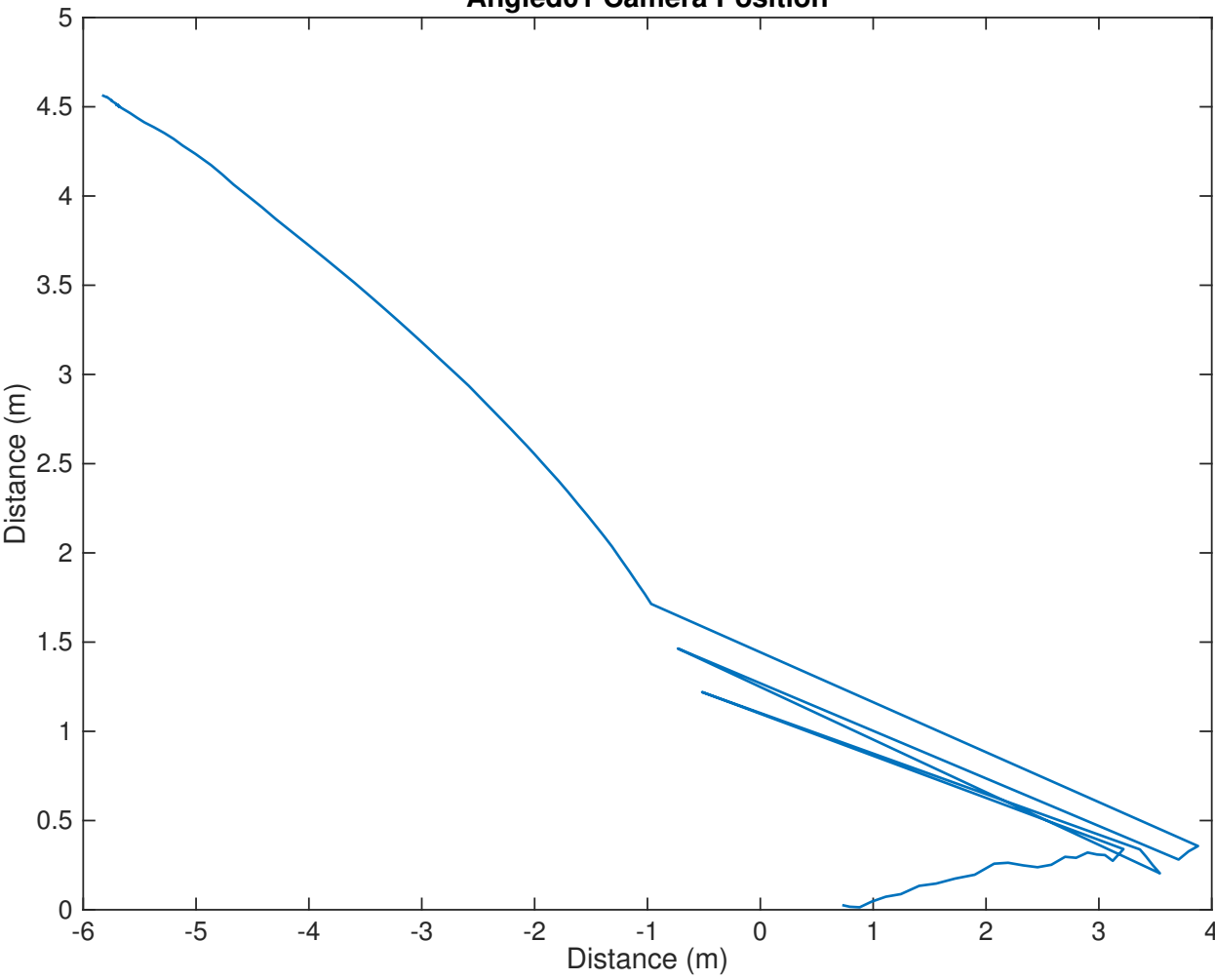
Angled01 Camera vs LIDAR Theta_1



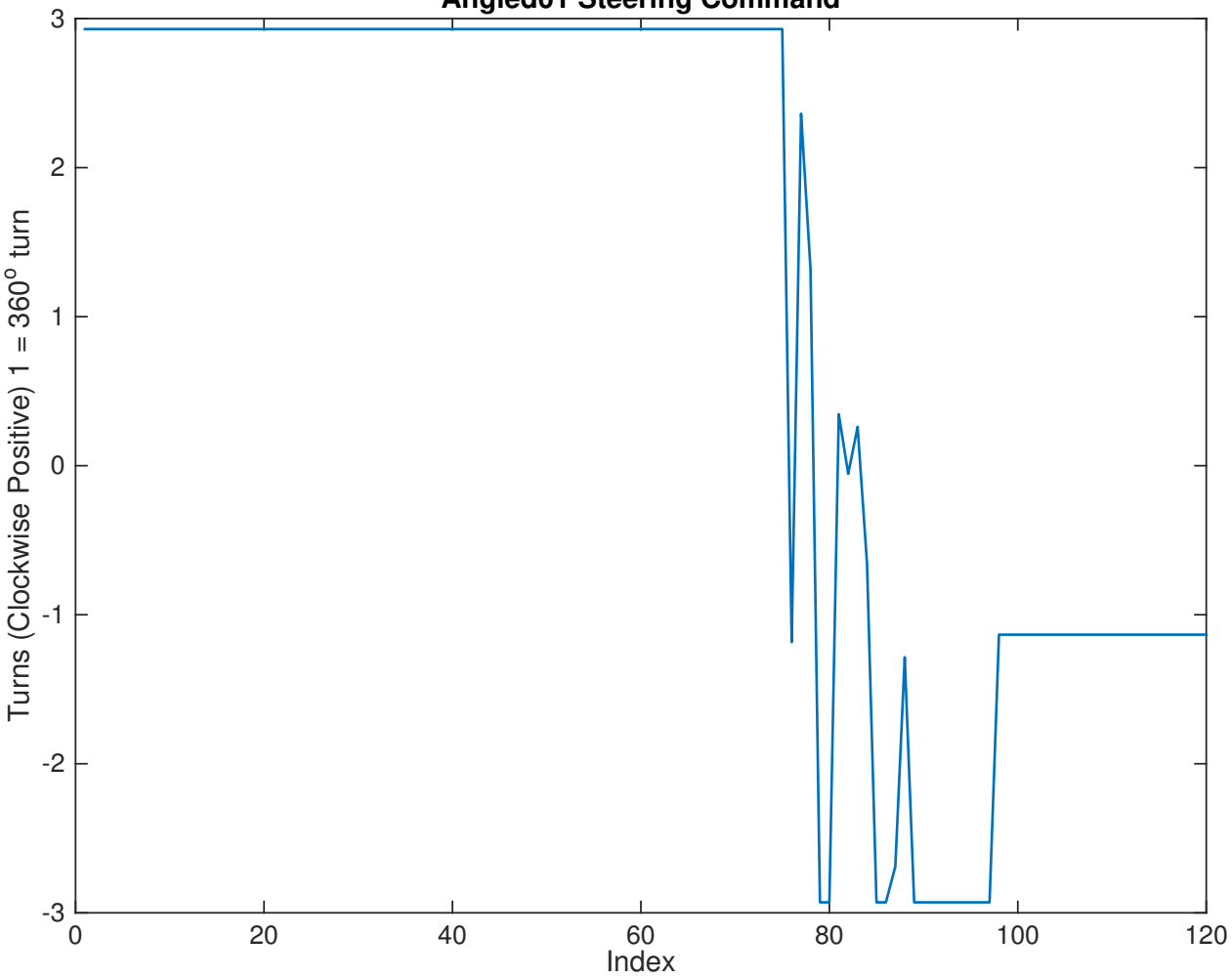
Angled01 Camera vs LIDAR Theta_2



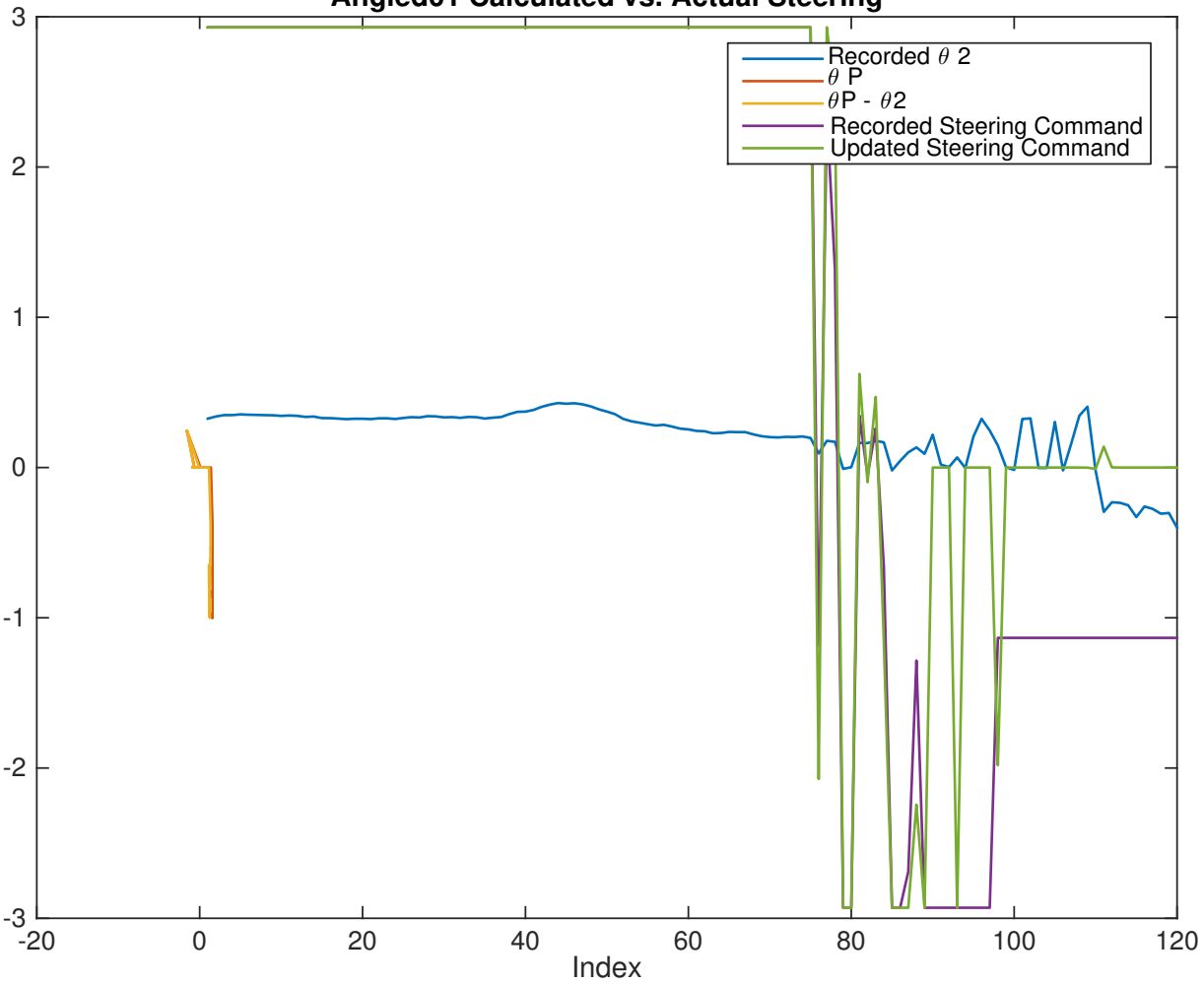
Angled01 Camera Position



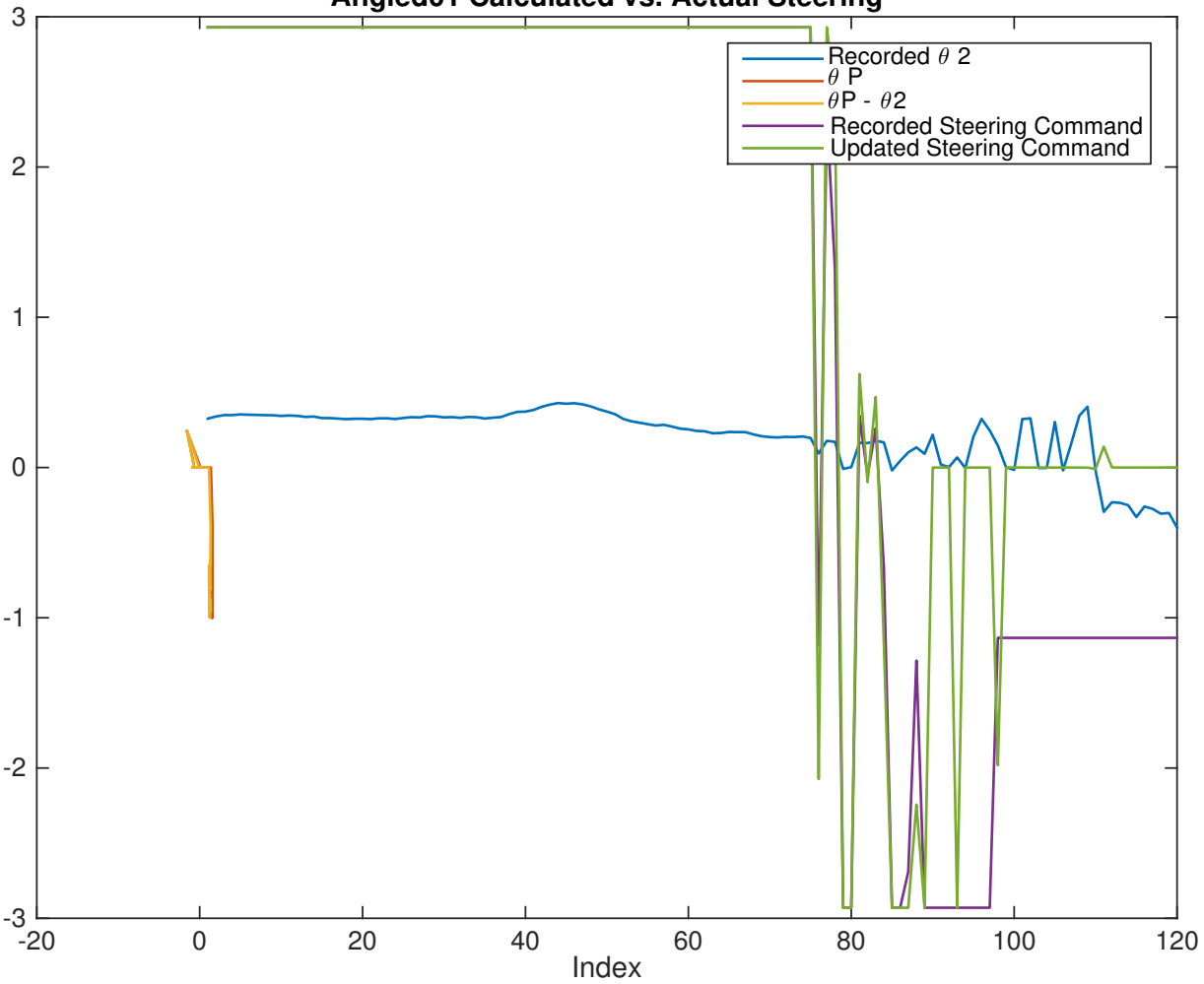
Angled01 Steering Command



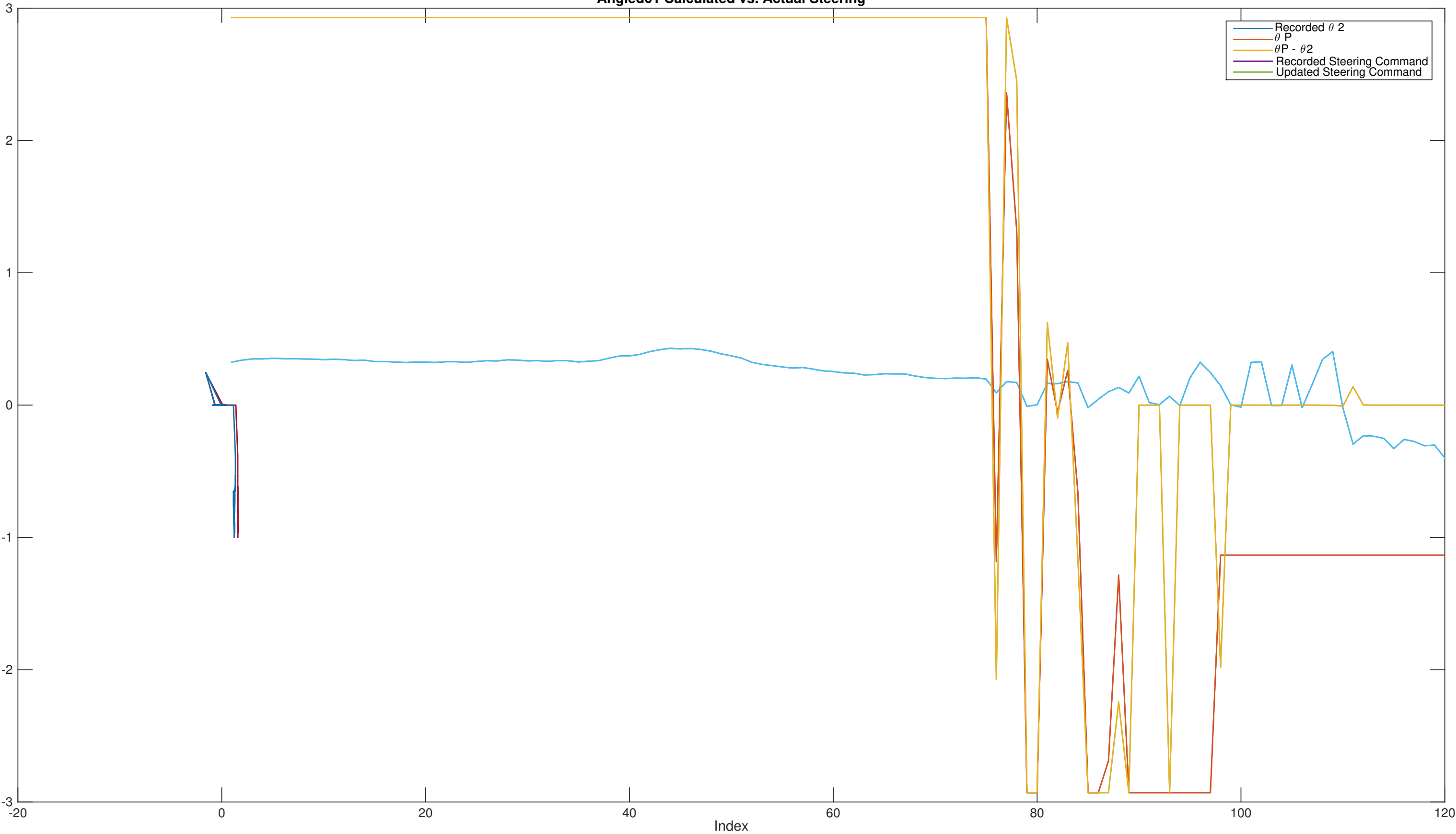
Angled01 Calculated vs. Actual Steering



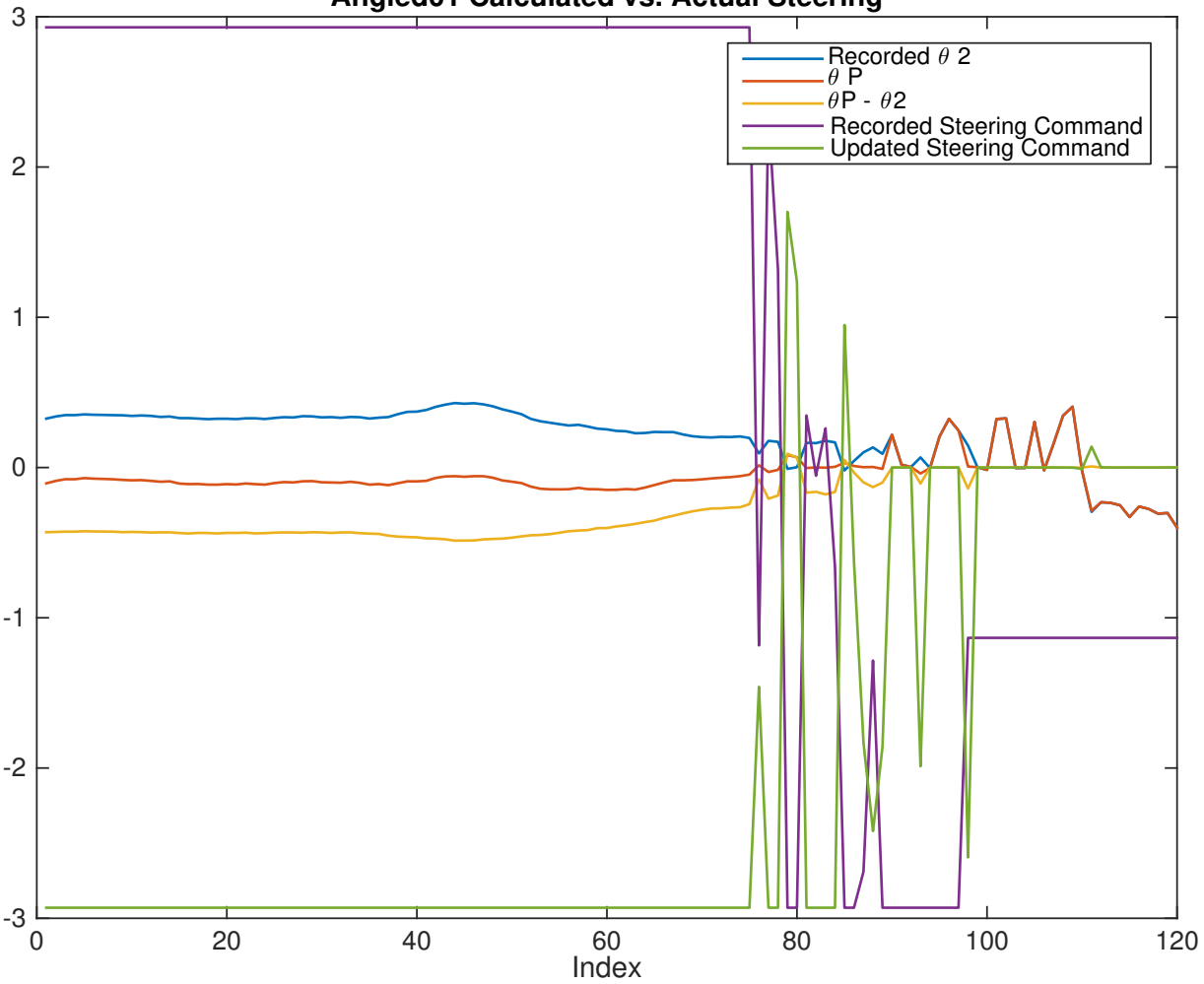
Angled01 Calculated vs. Actual Steering



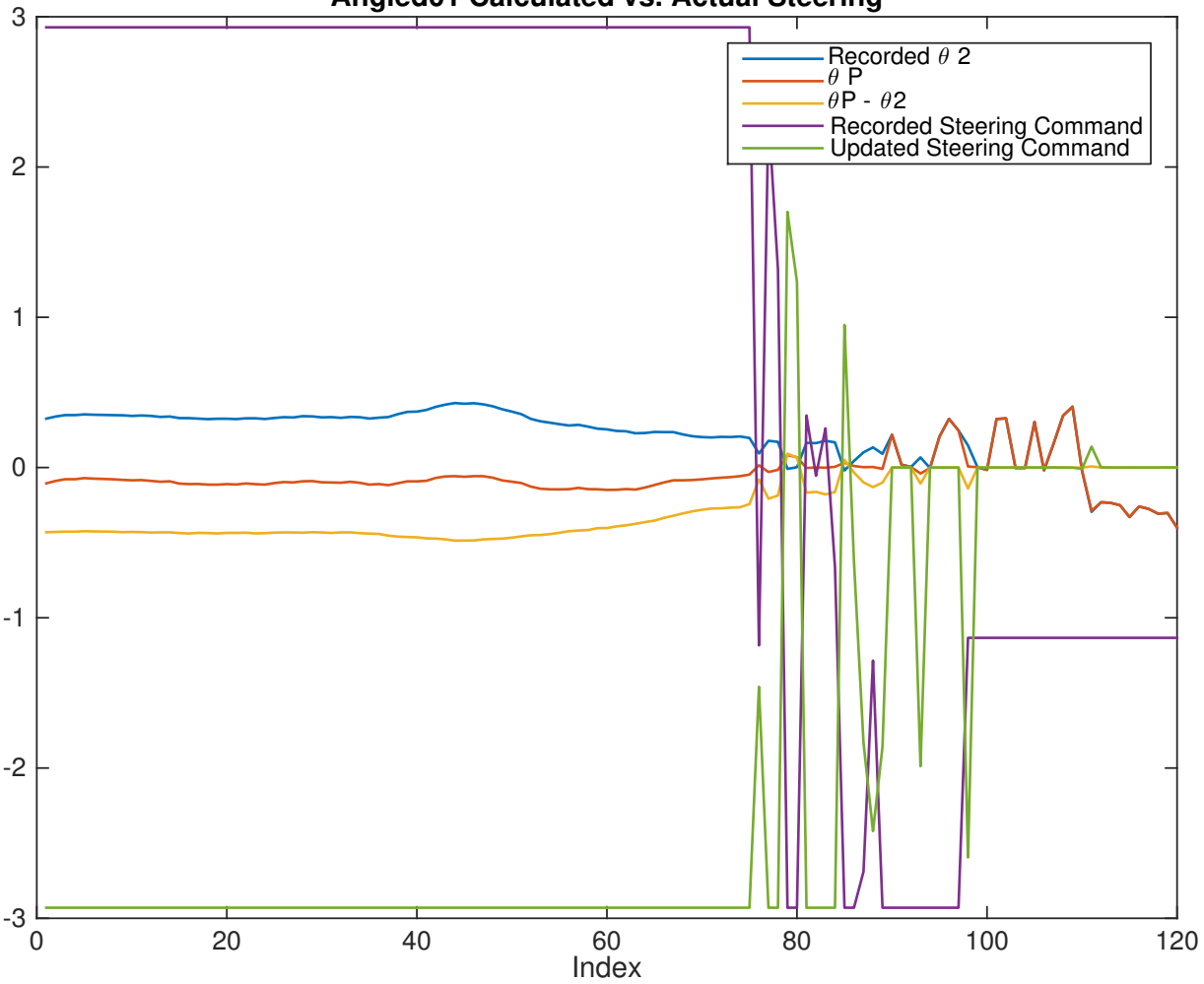
Angled01 Calculated vs. Actual Steering



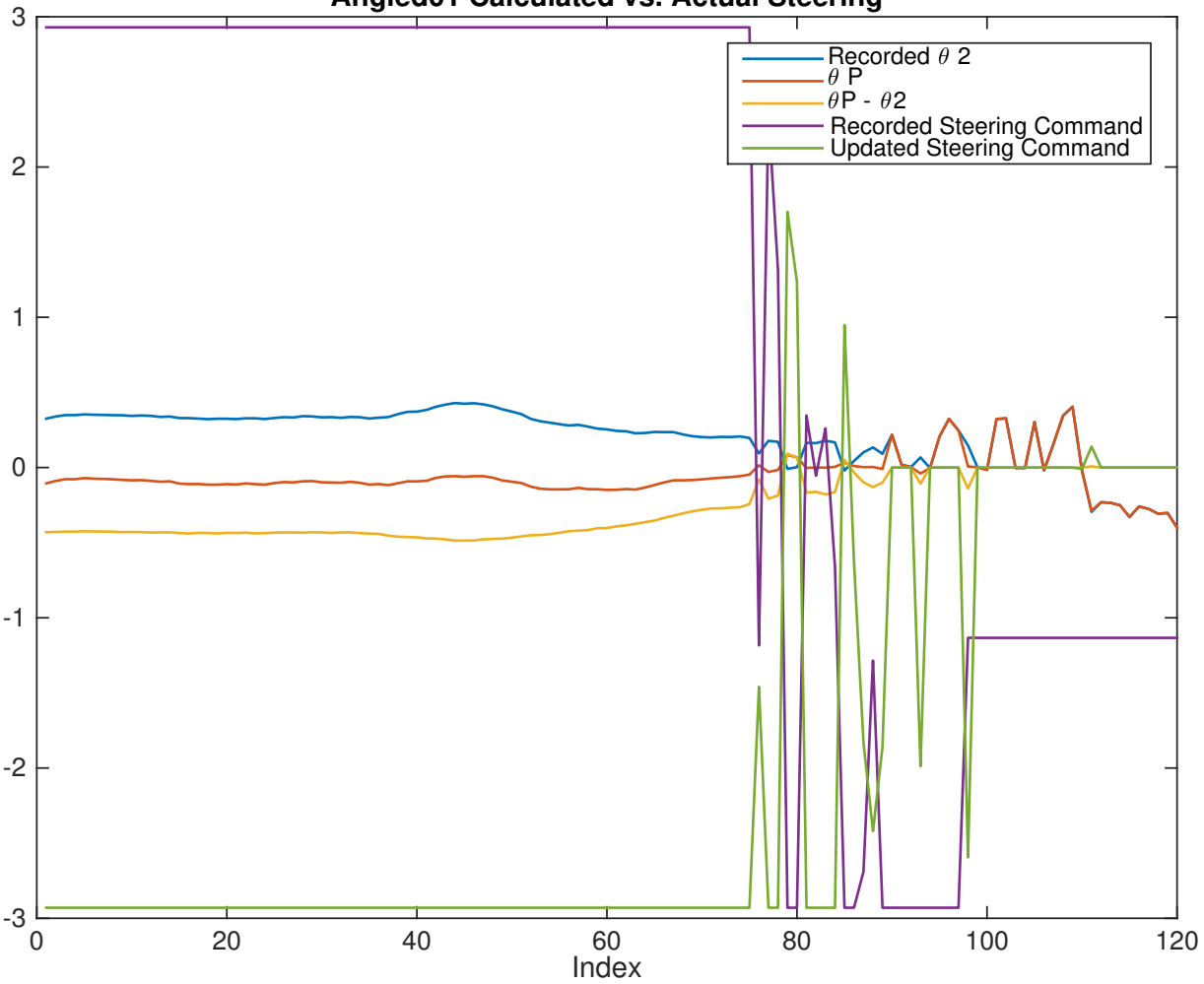
Angled01 Calculated vs. Actual Steering



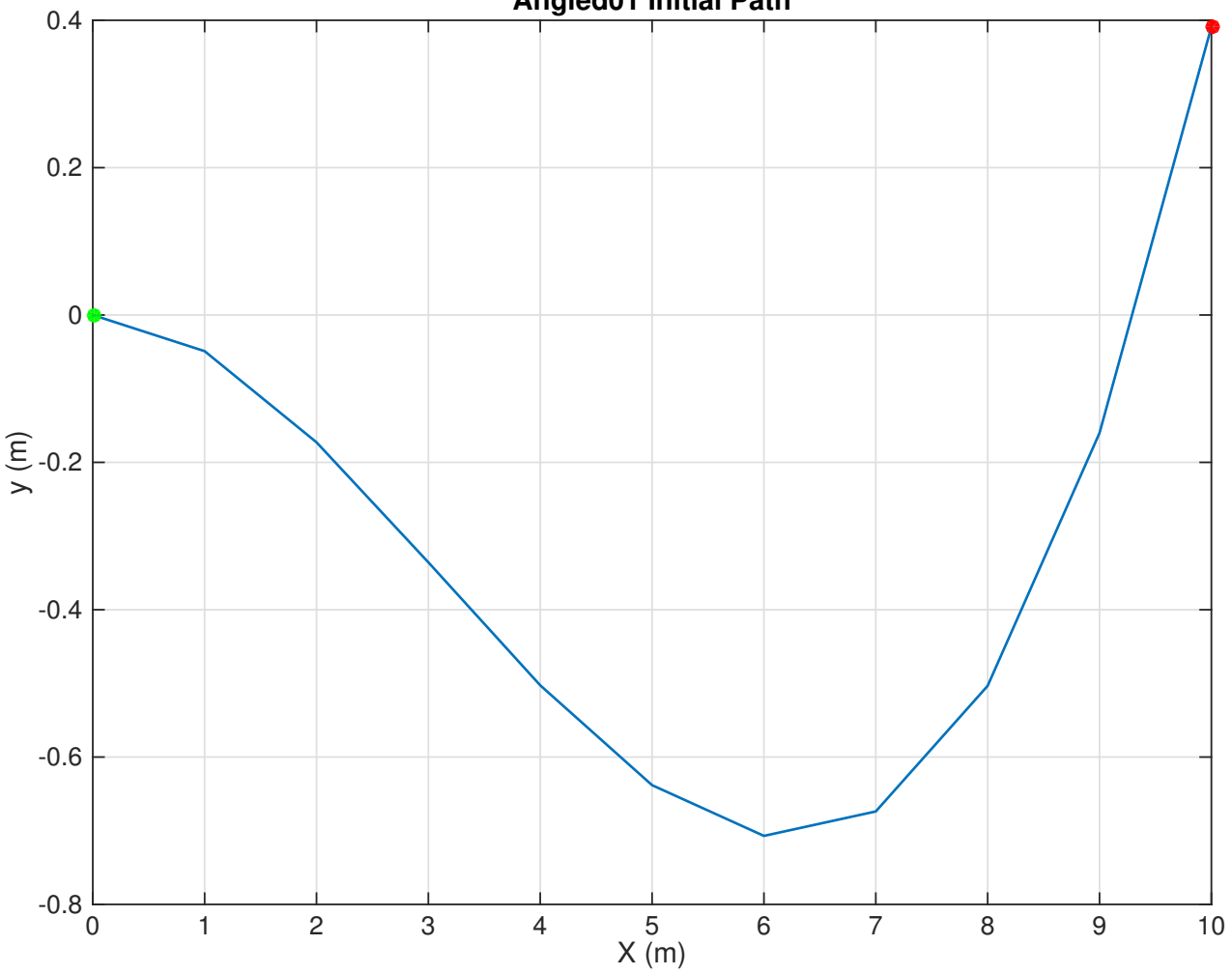
Angled01 Calculated vs. Actual Steering



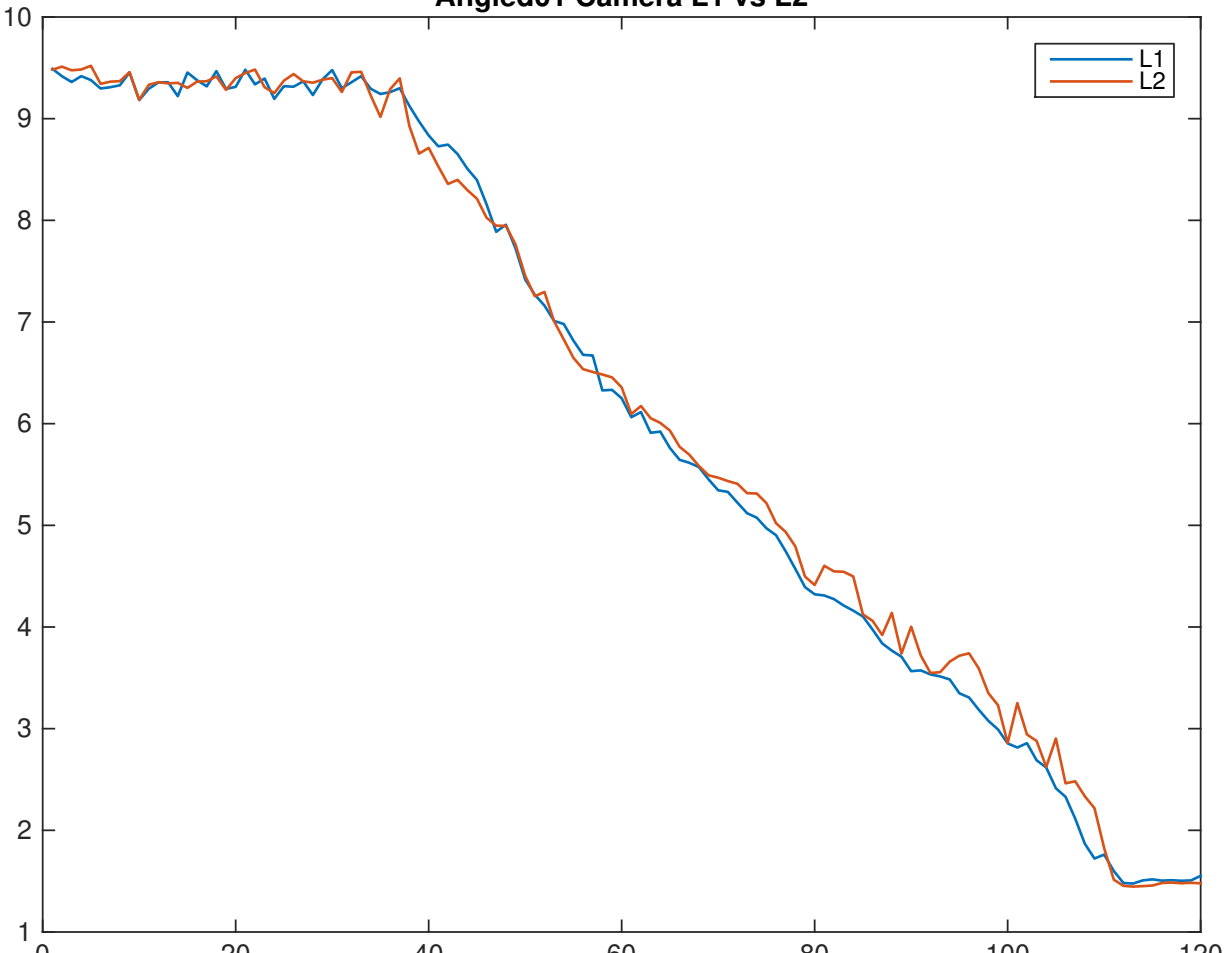
Angled01 Calculated vs. Actual Steering



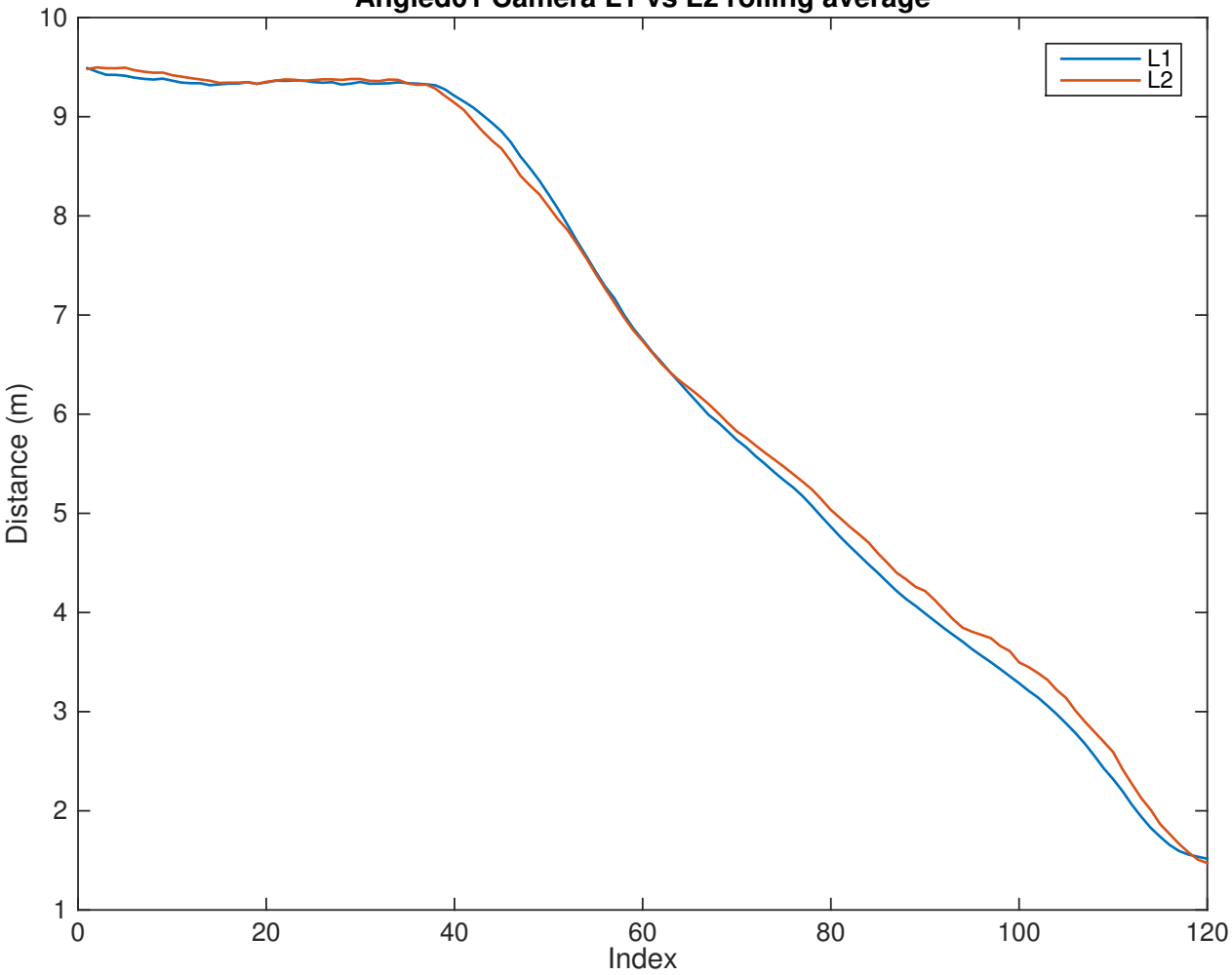
Angled01 Initial Path



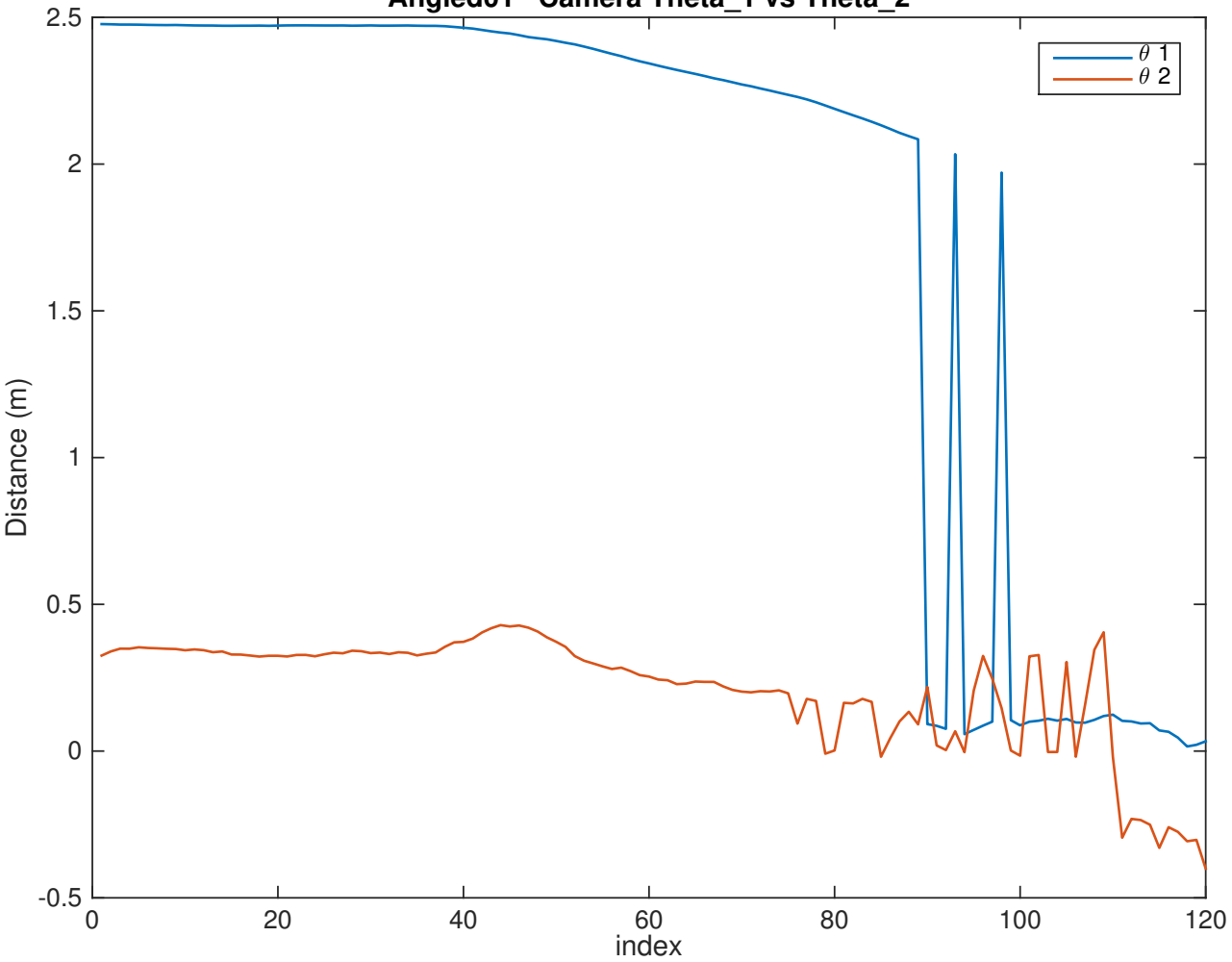
Angled01 Camera L1 vs L2



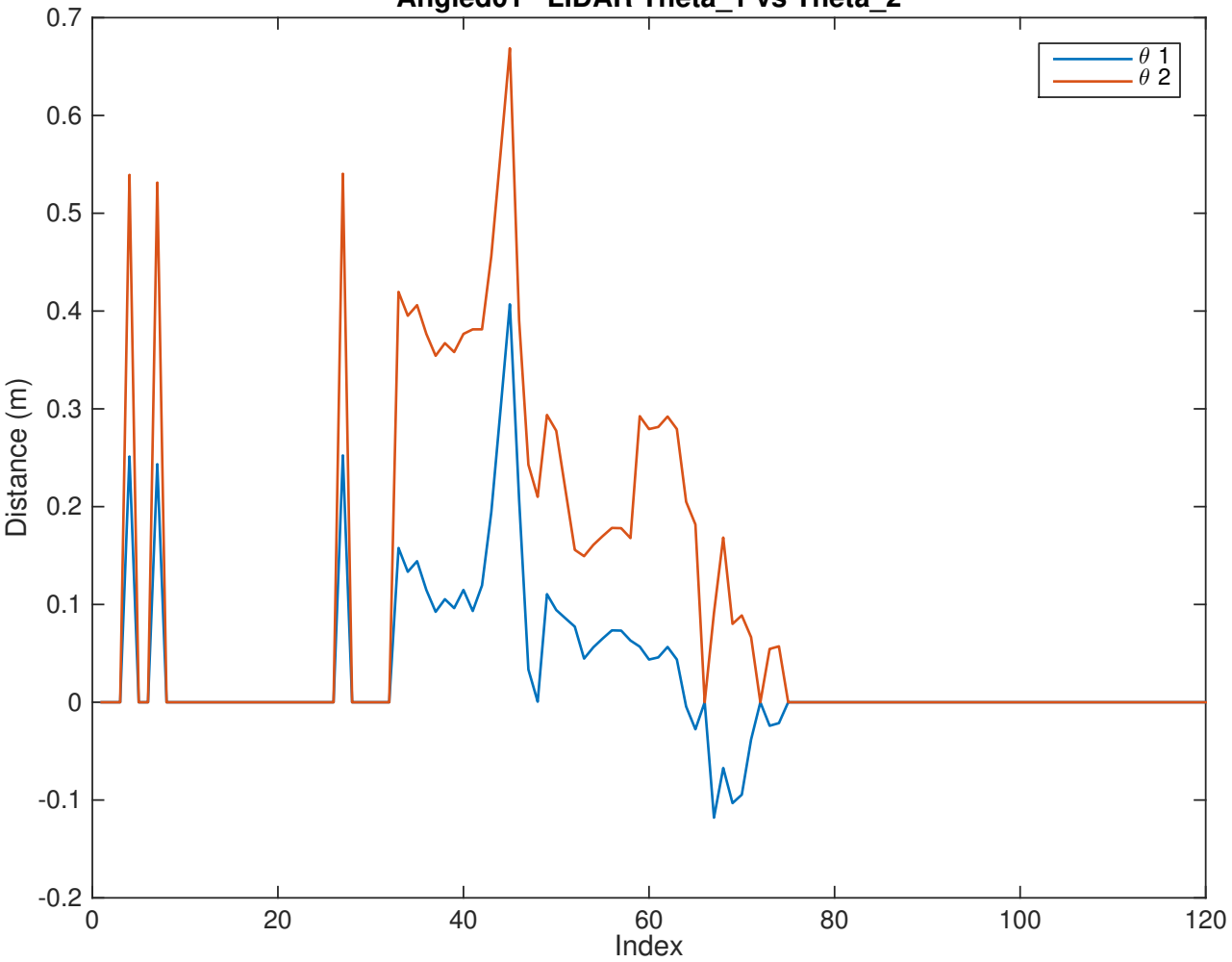
Angled01 Camera L1 vs L2 rolling average



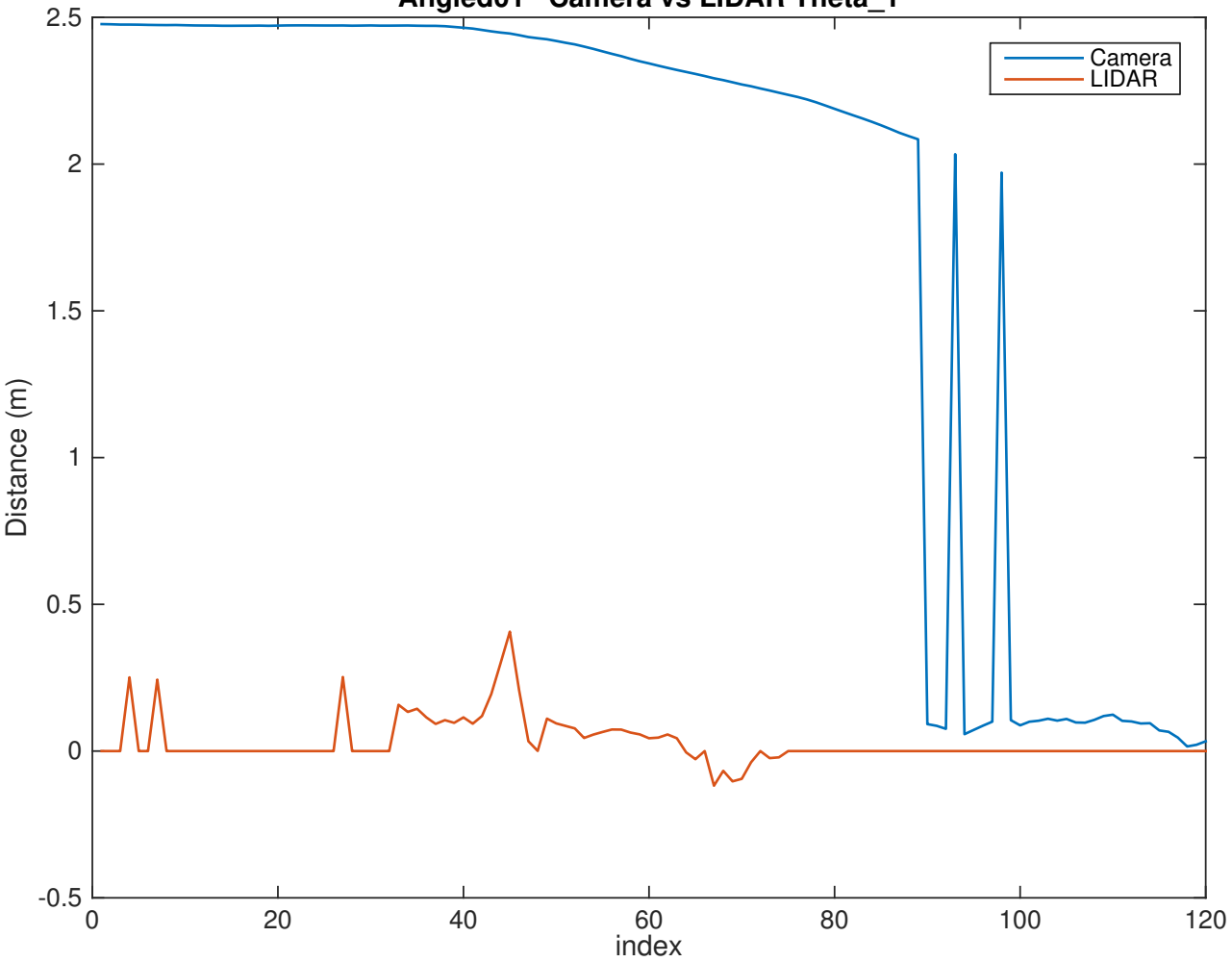
Angled01 Camera Theta_1 vs Theta_2



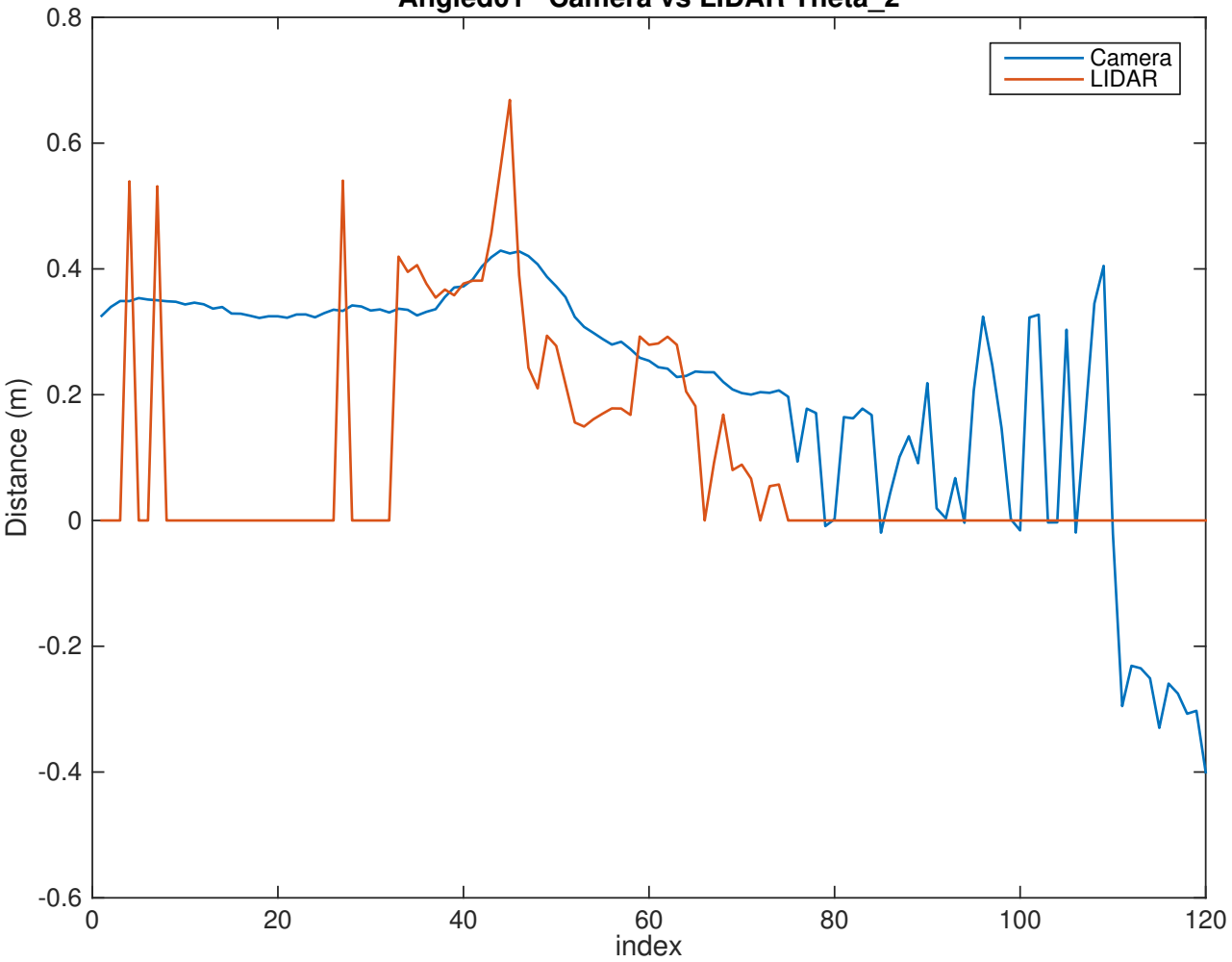
Angled01 LIDAR Theta_1 vs Theta_2



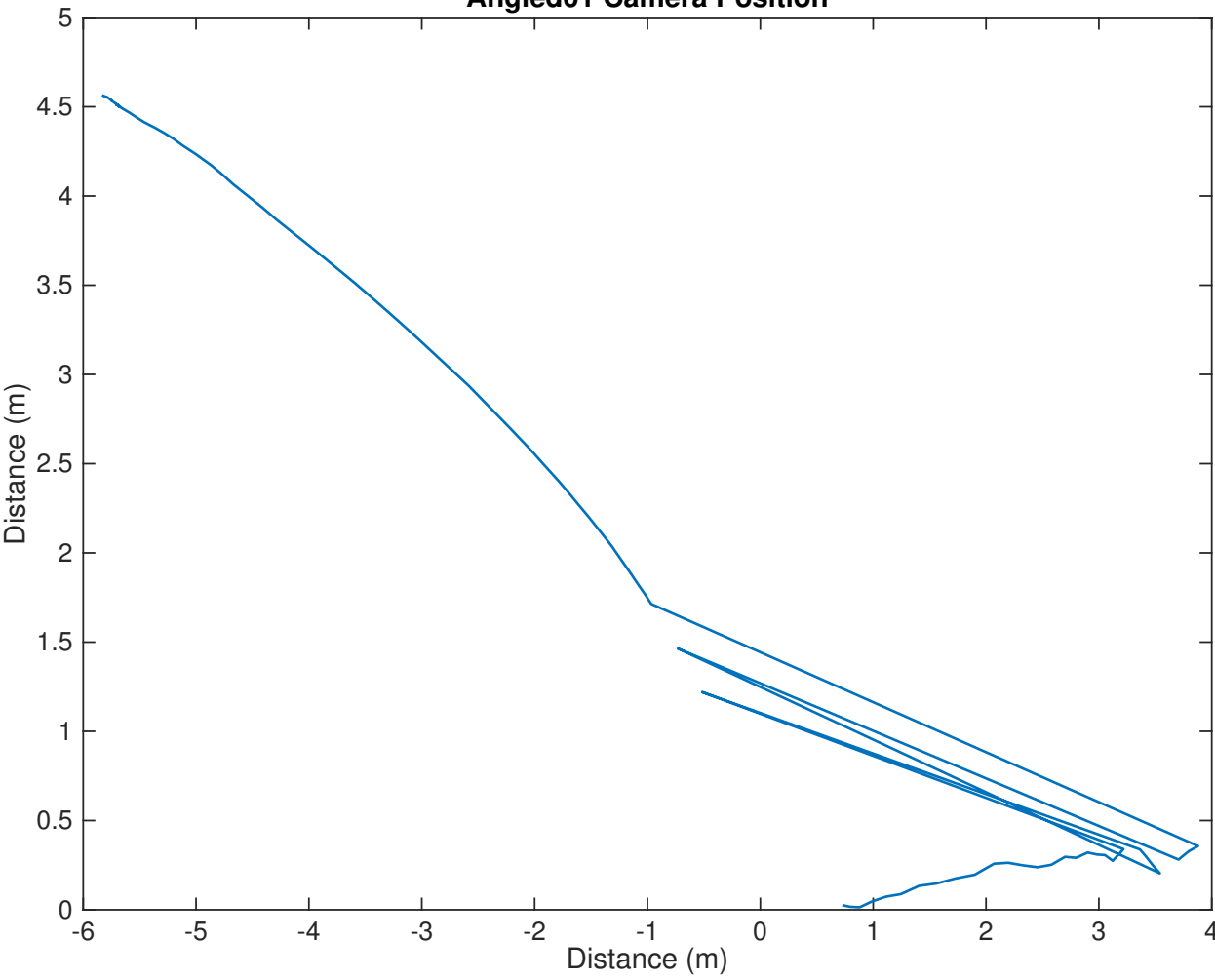
Angled01 Camera vs LIDAR Theta_1



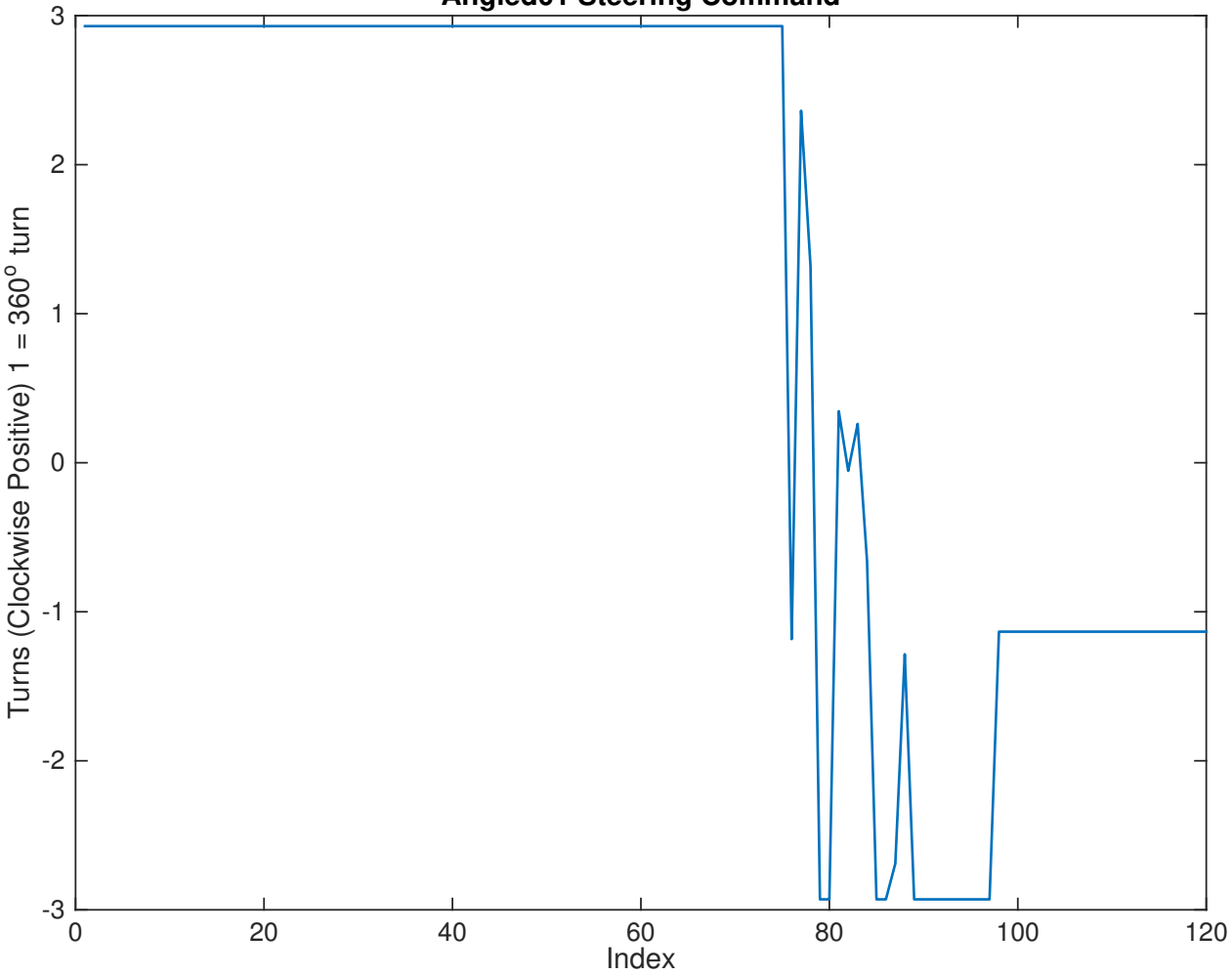
Angled01 Camera vs LIDAR Theta_2



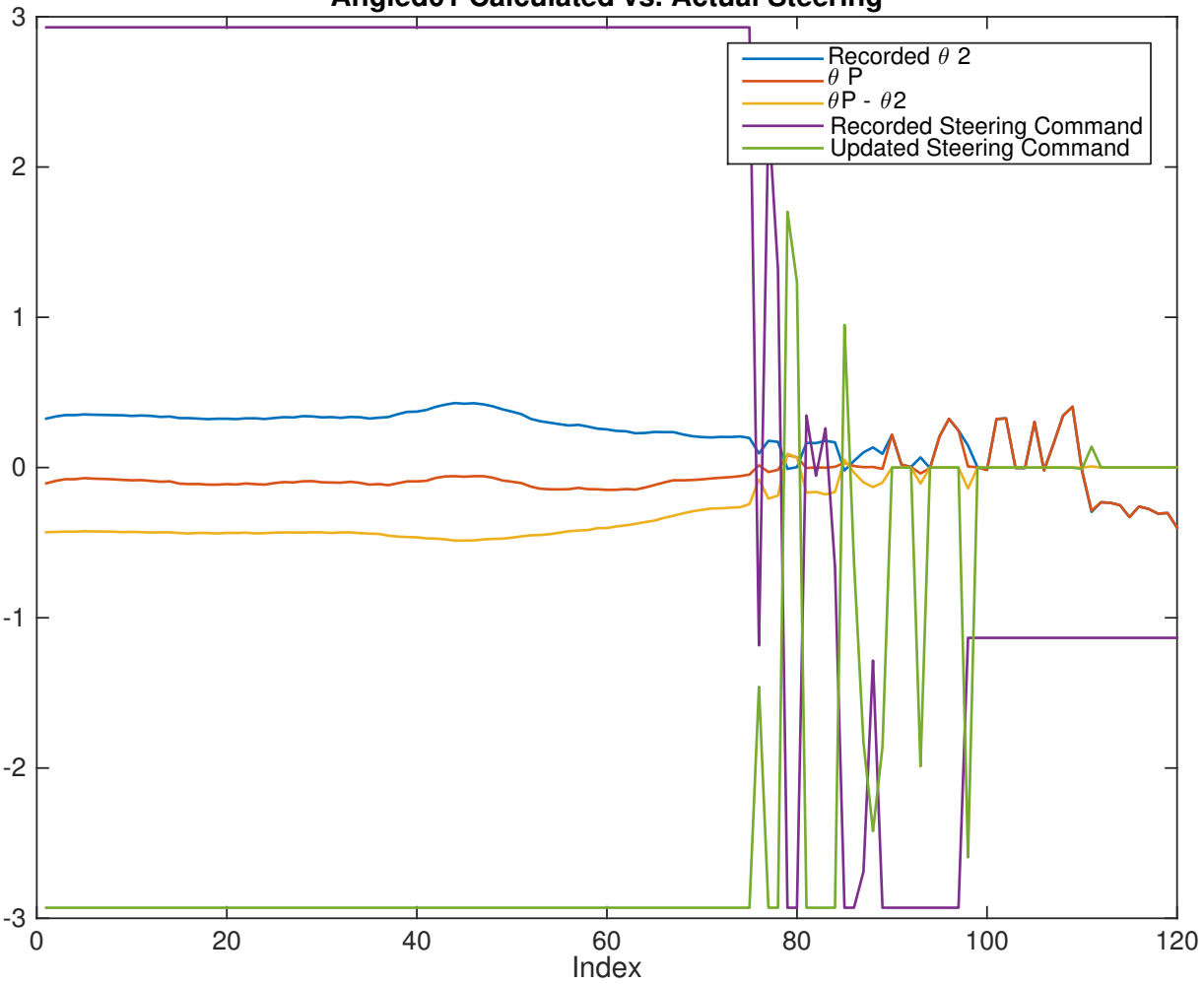
Angled01 Camera Position



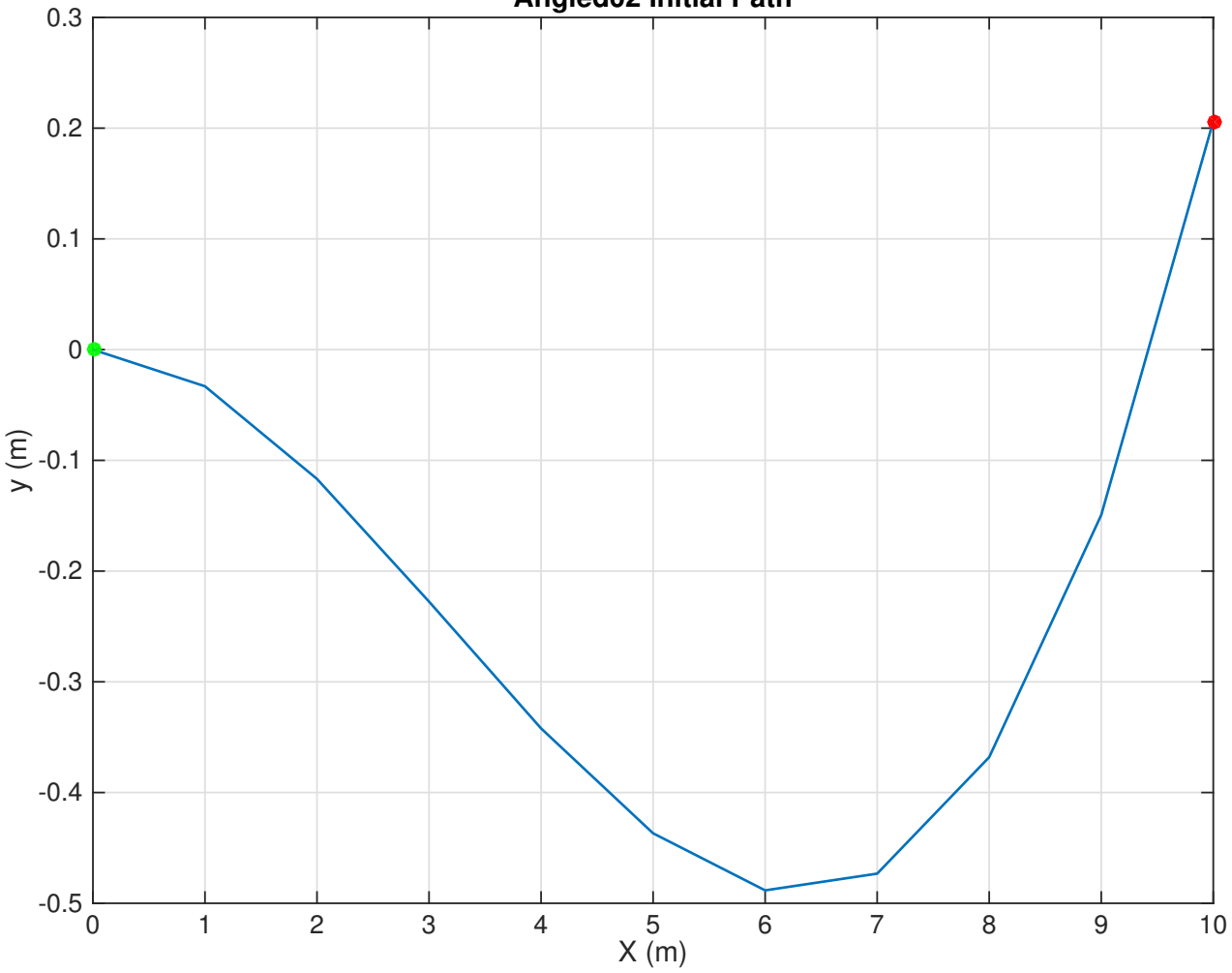
Angled01 Steering Command



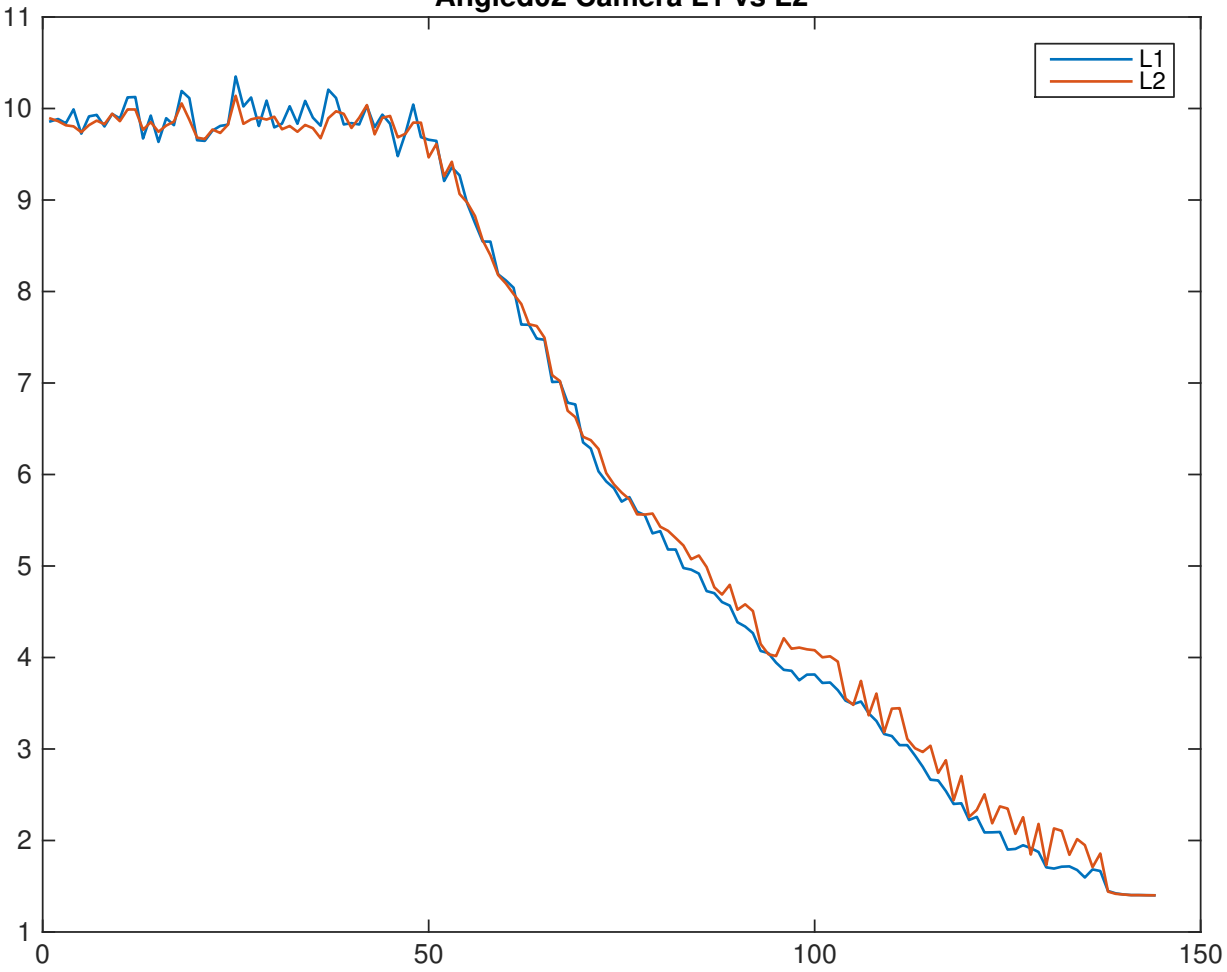
Angled01 Calculated vs. Actual Steering



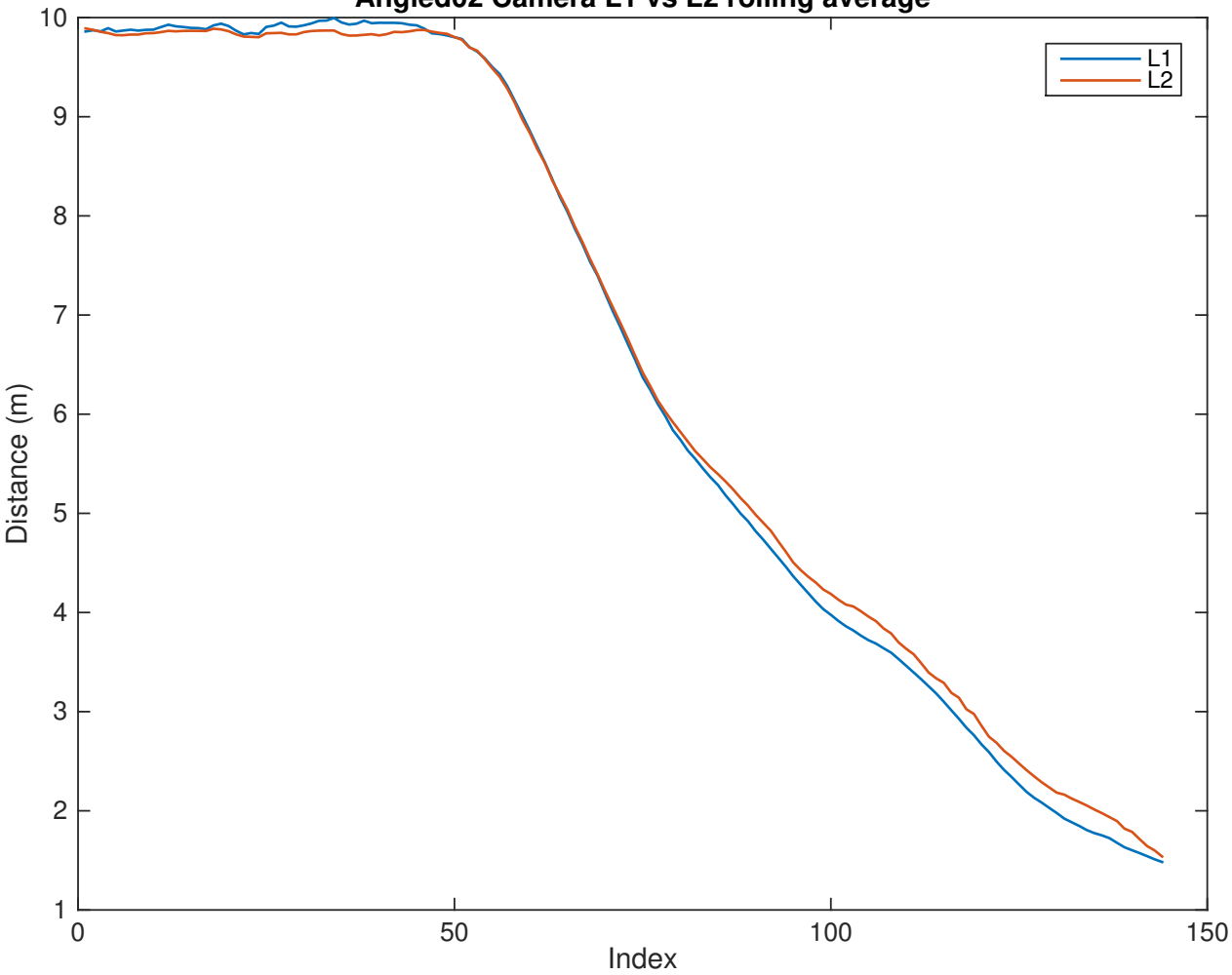
Angled02 Initial Path



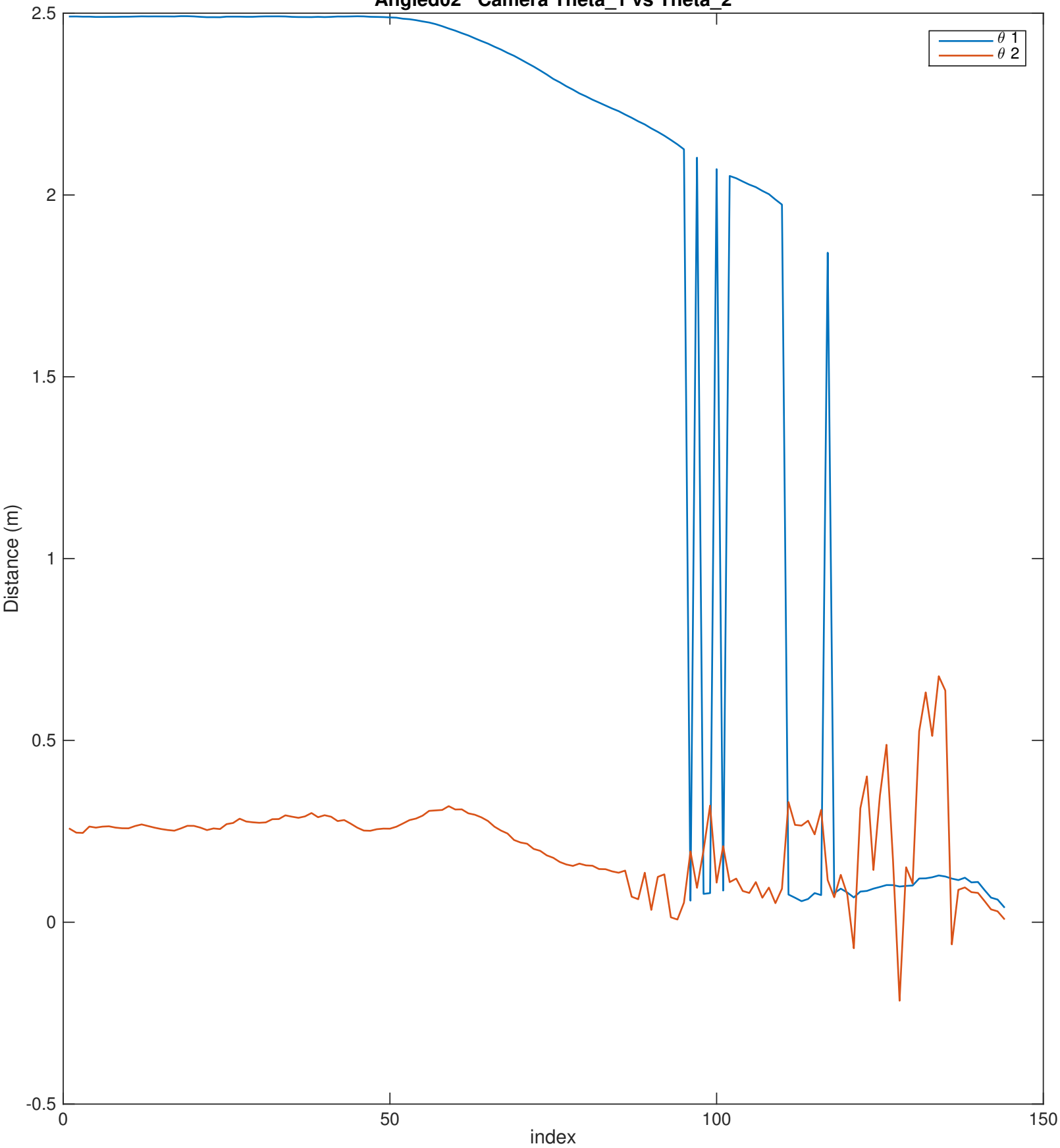
Angled02 Camera L1 vs L2



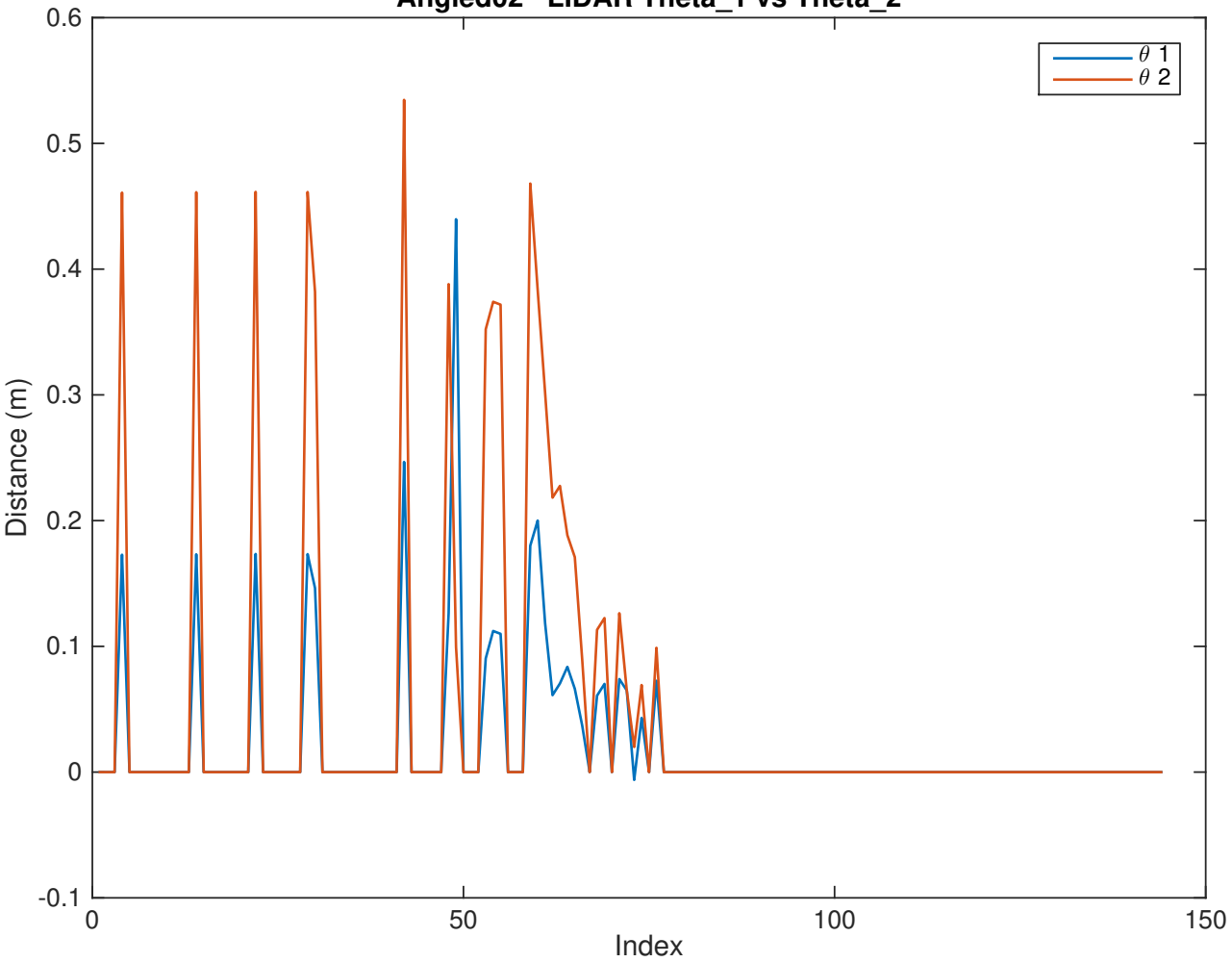
Angled02 Camera L1 vs L2 rolling average



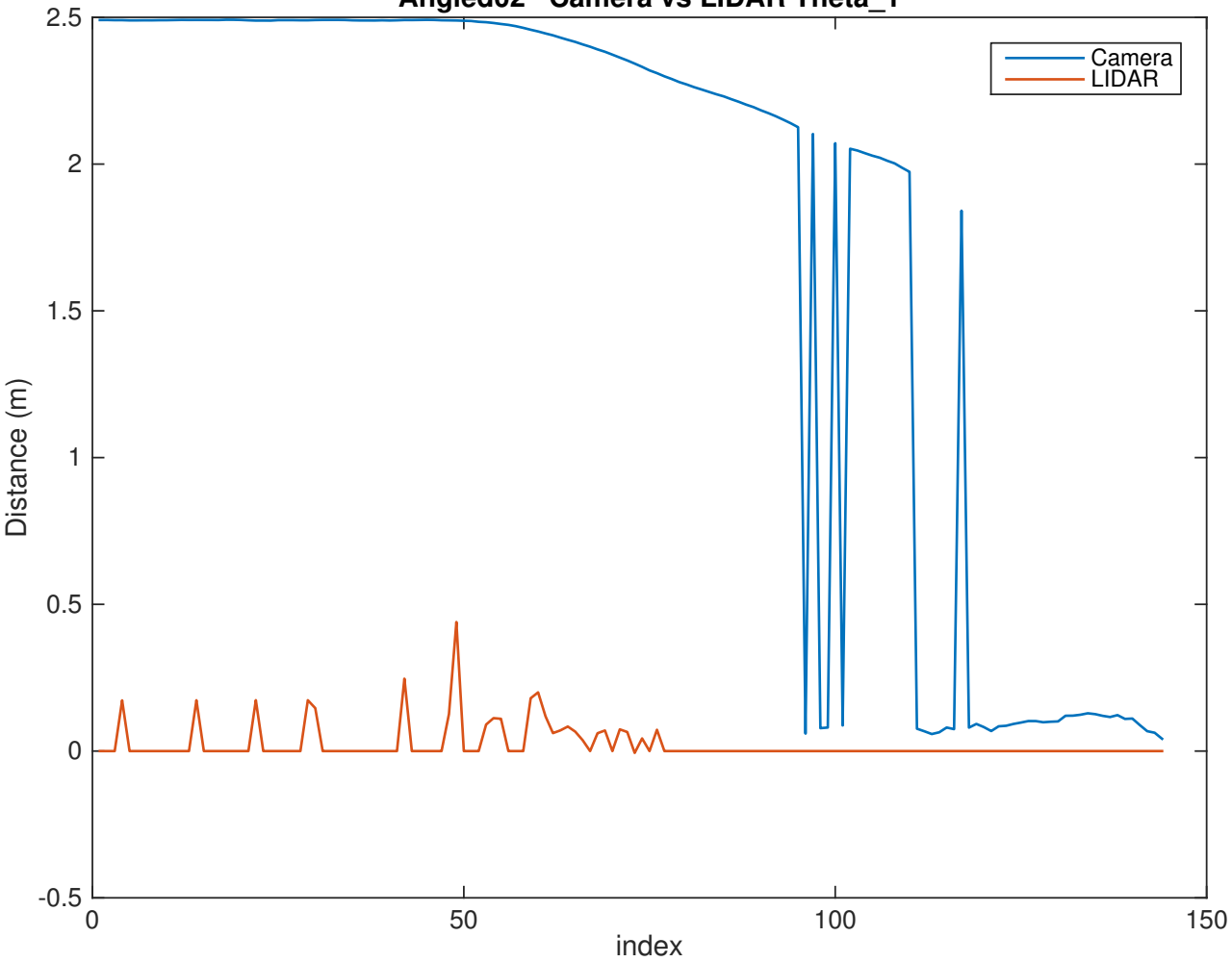
Angled02 Camera Theta_1 vs Theta_2



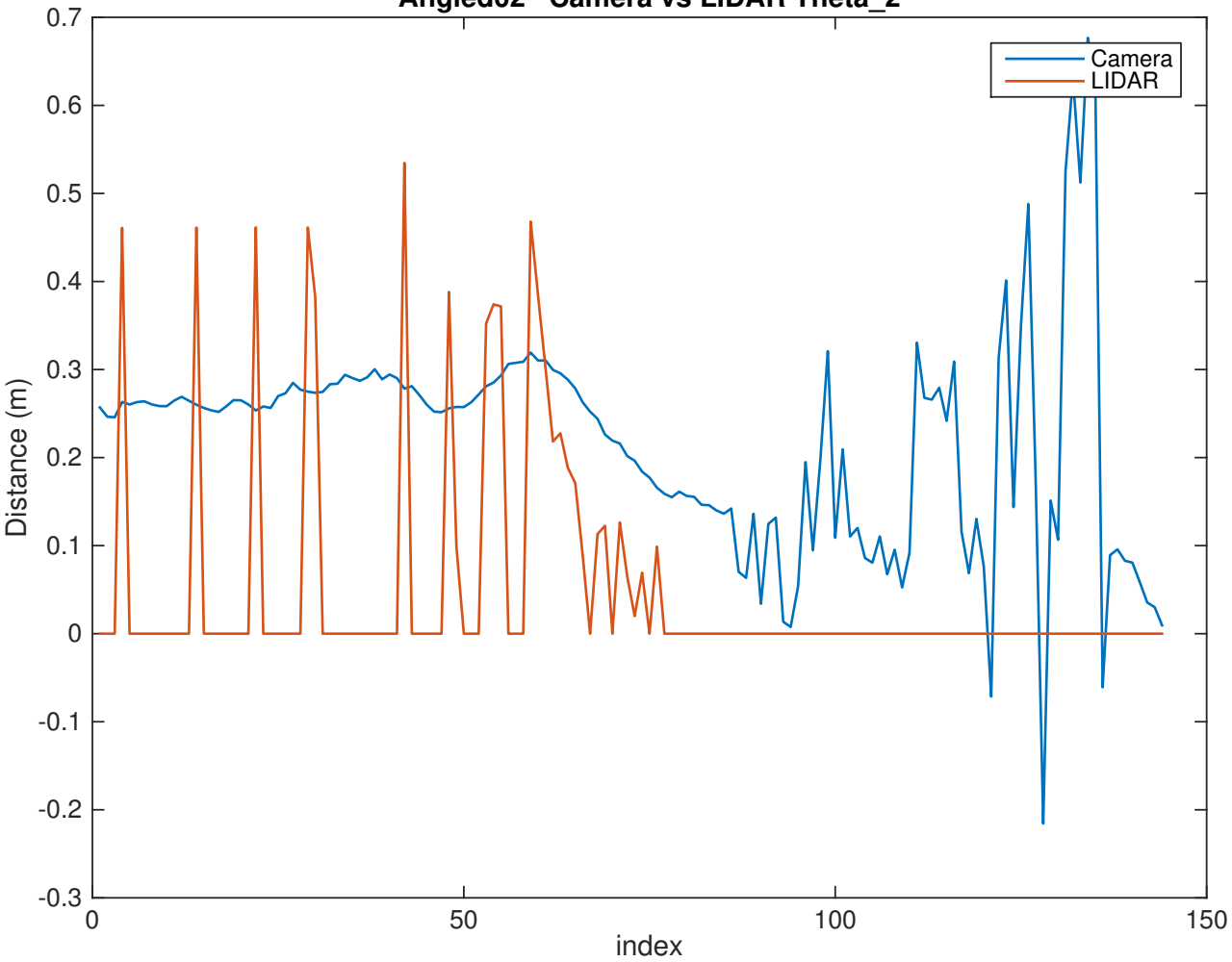
Angled02 LIDAR Theta_1 vs Theta_2



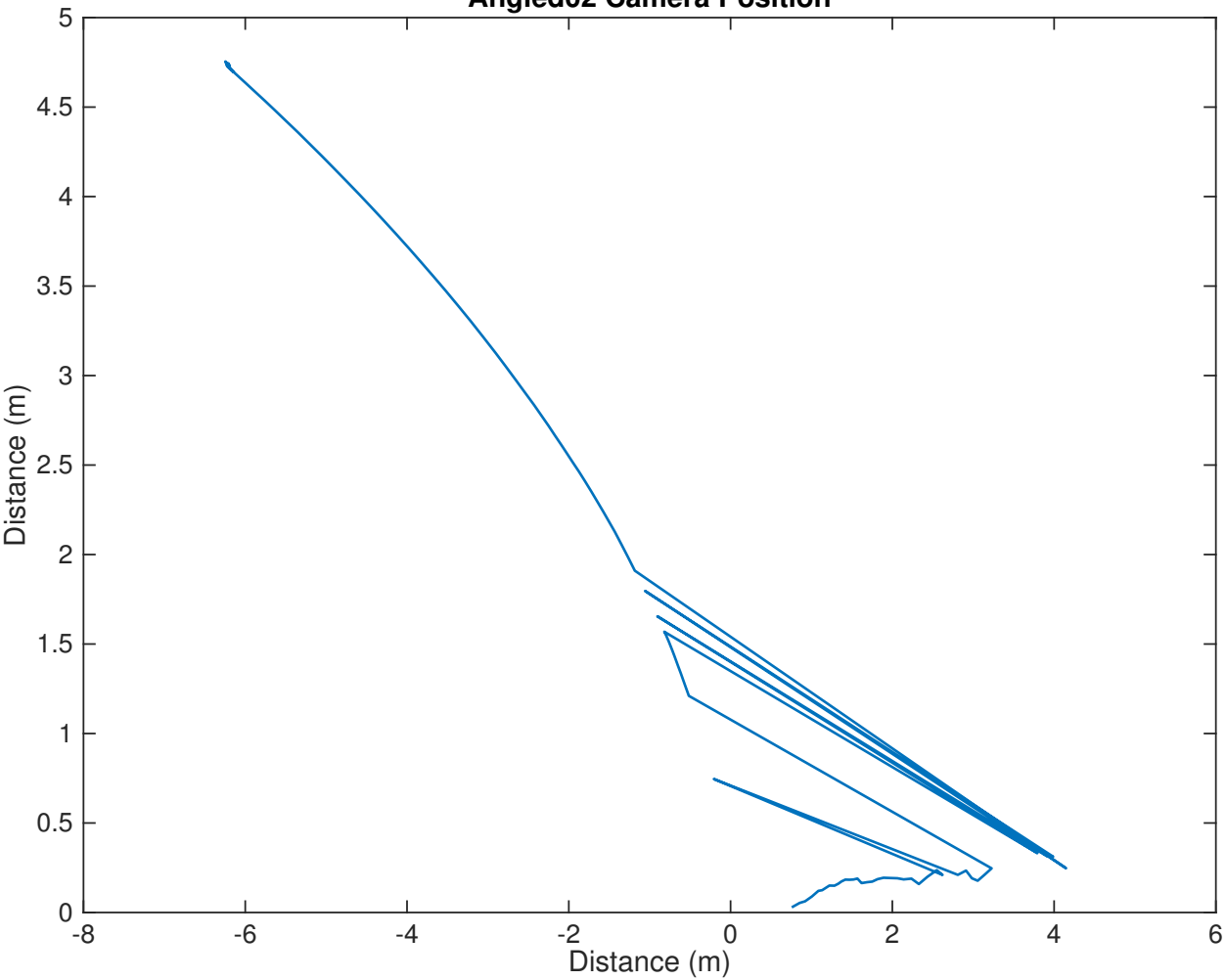
Angled02 Camera vs LIDAR Theta_1



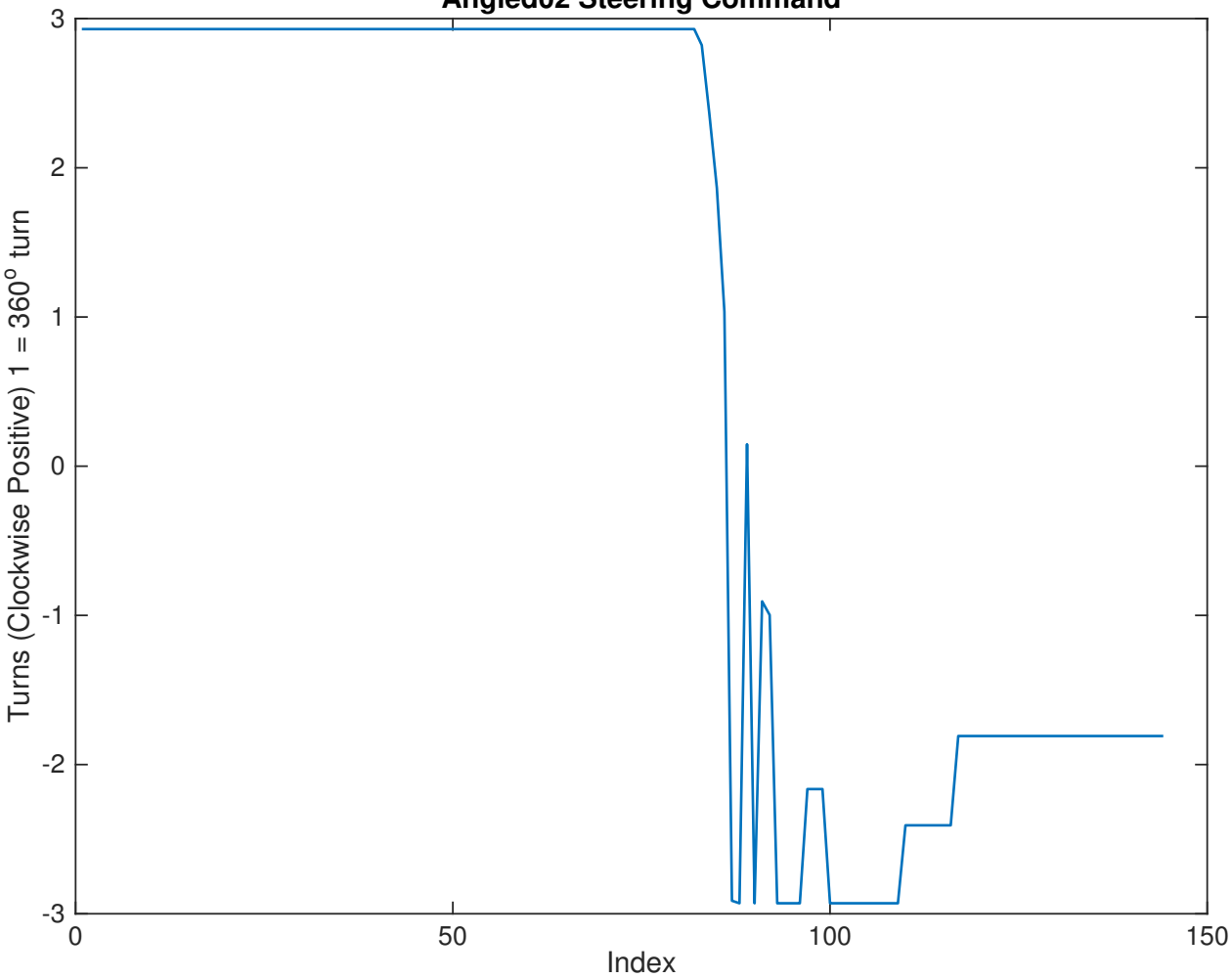
Angled02 Camera vs LIDAR Theta_2



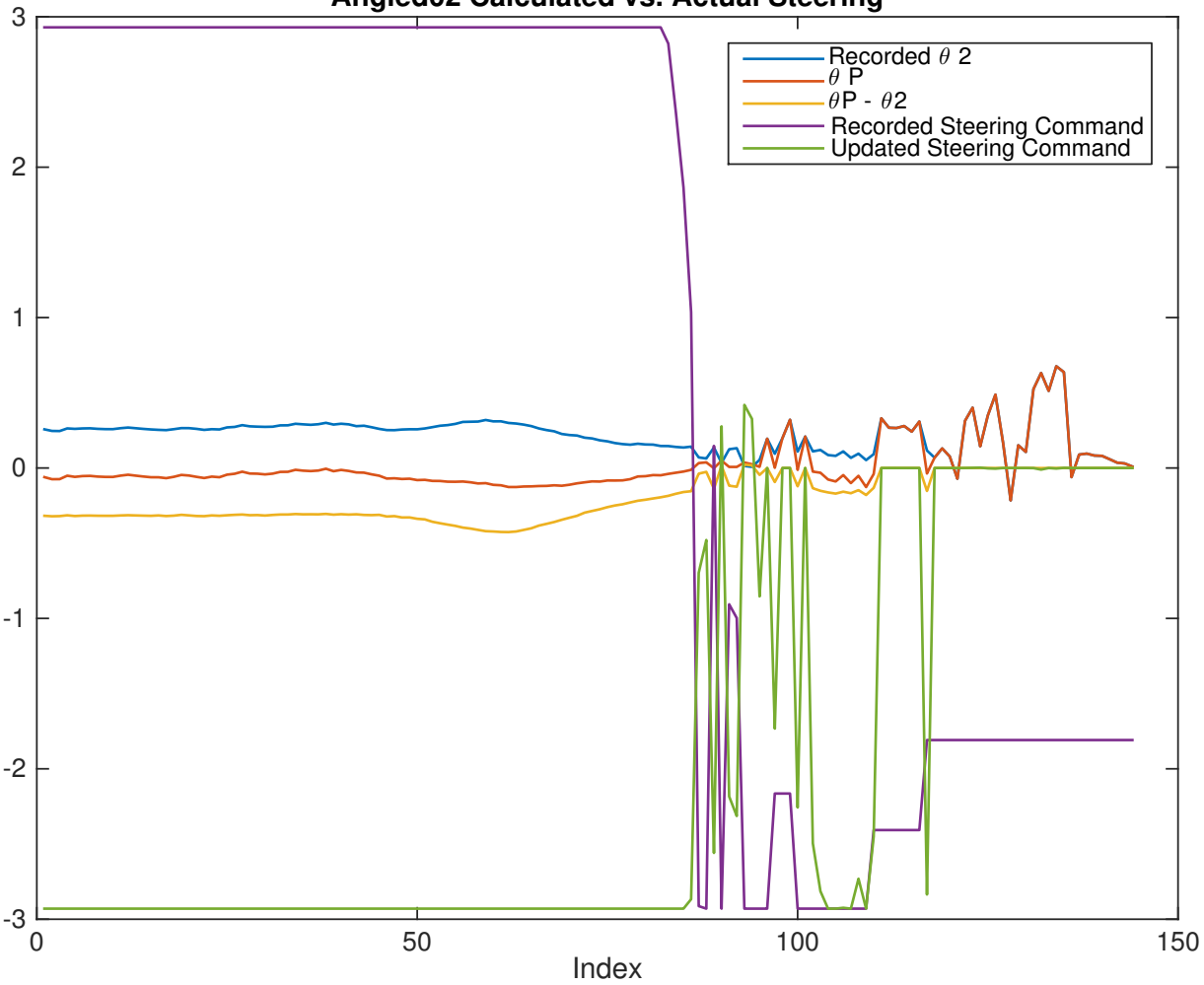
Angled02 Camera Position



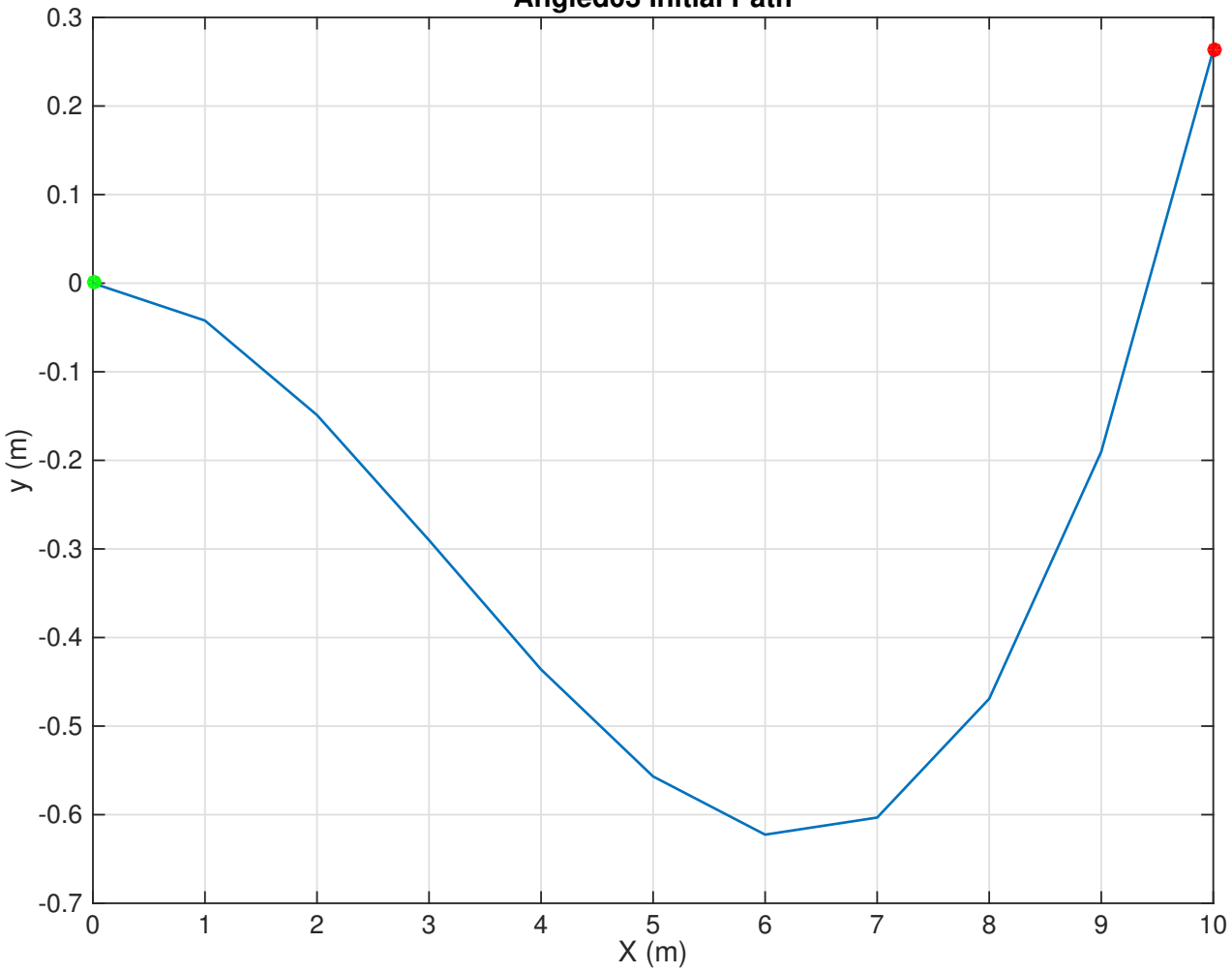
Angled02 Steering Command



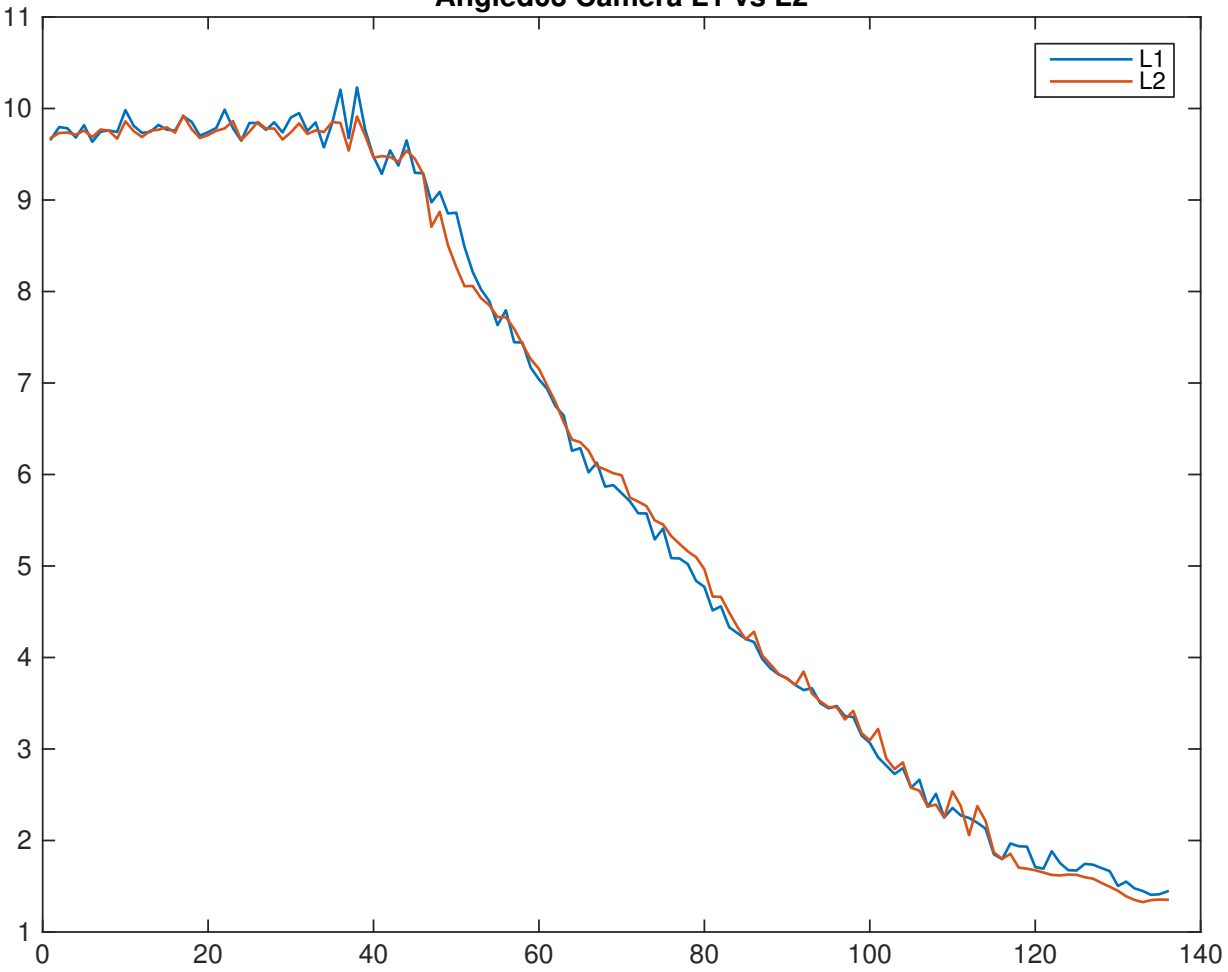
Angled02 Calculated vs. Actual Steering



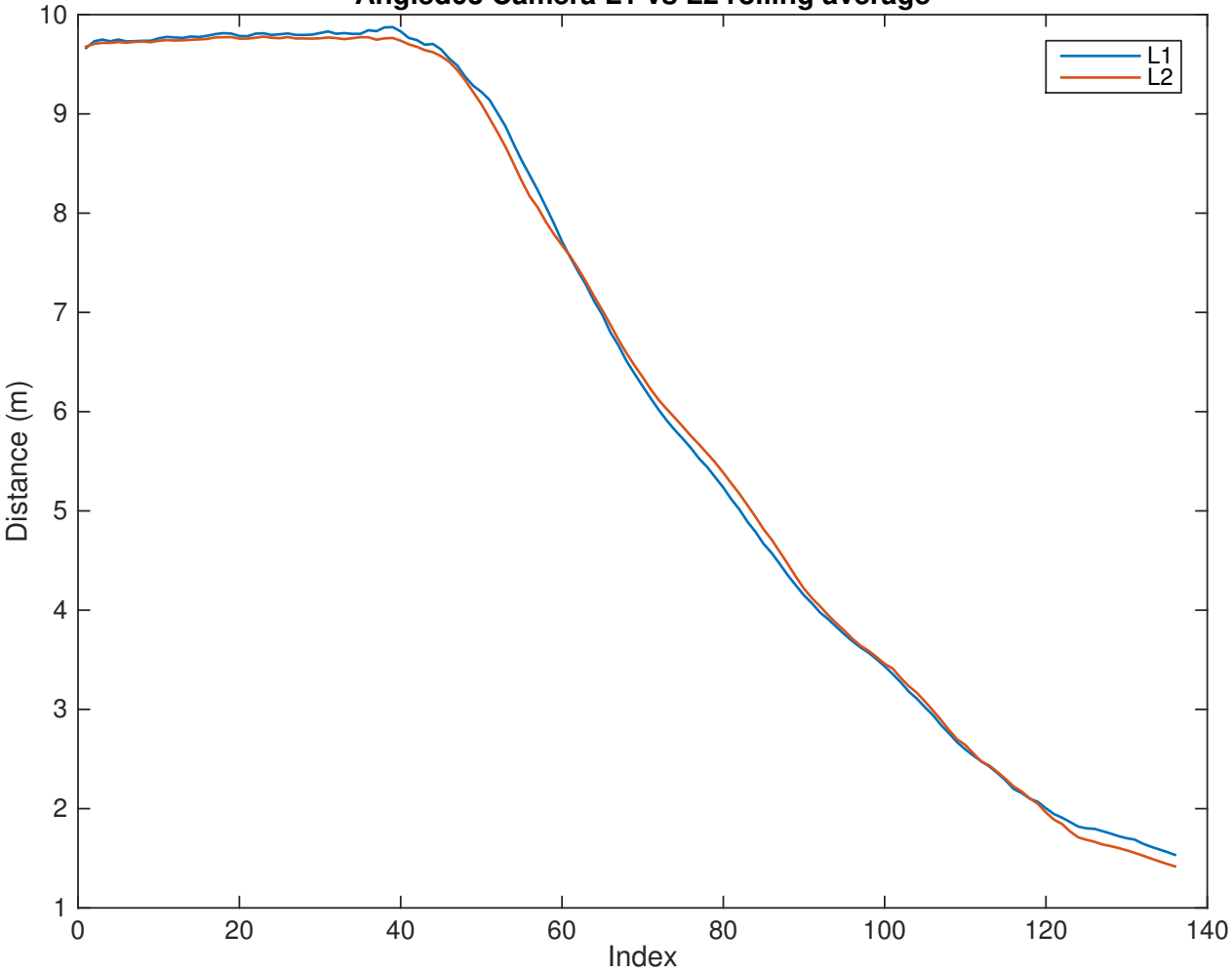
Angled03 Initial Path



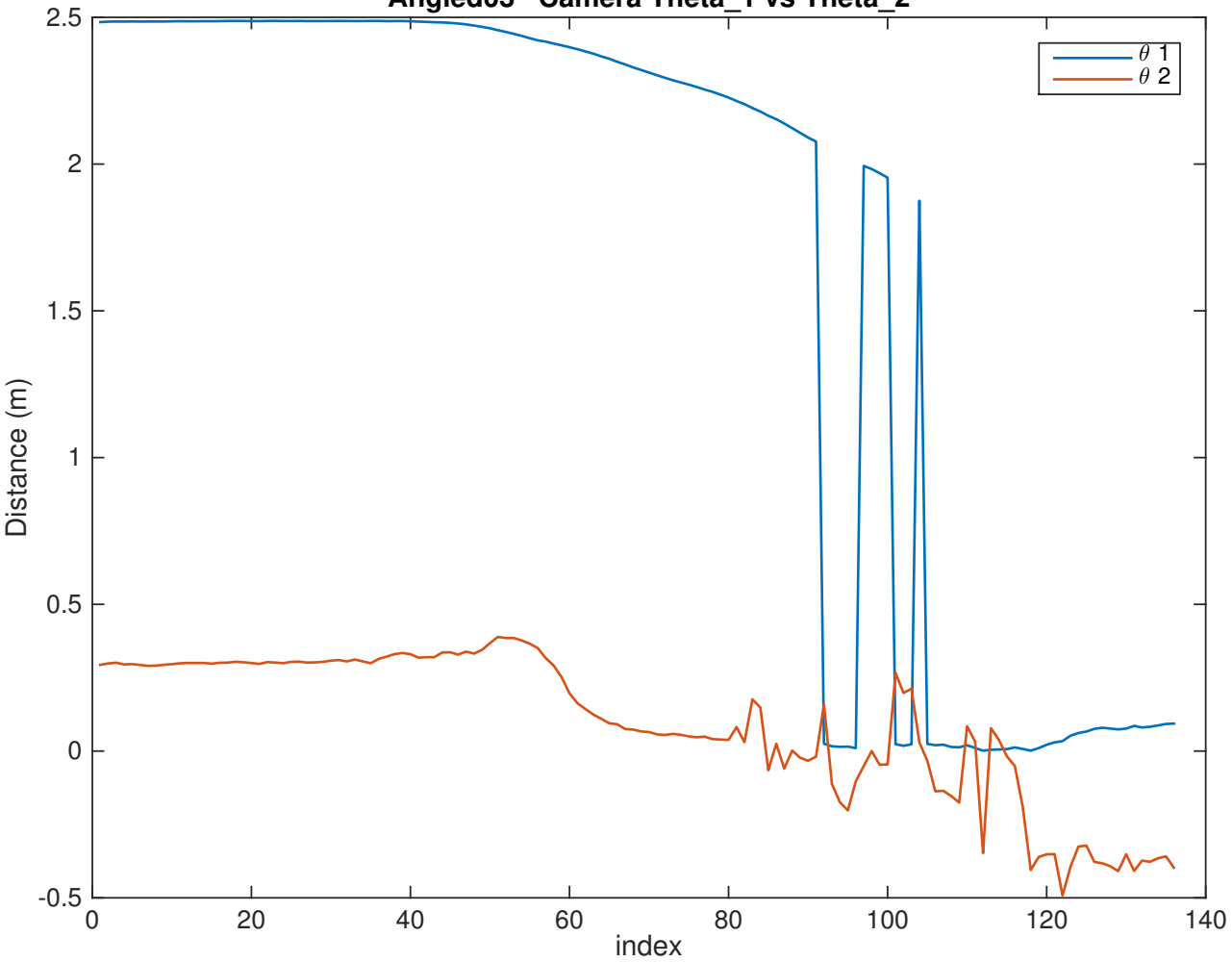
Angled03 Camera L1 vs L2



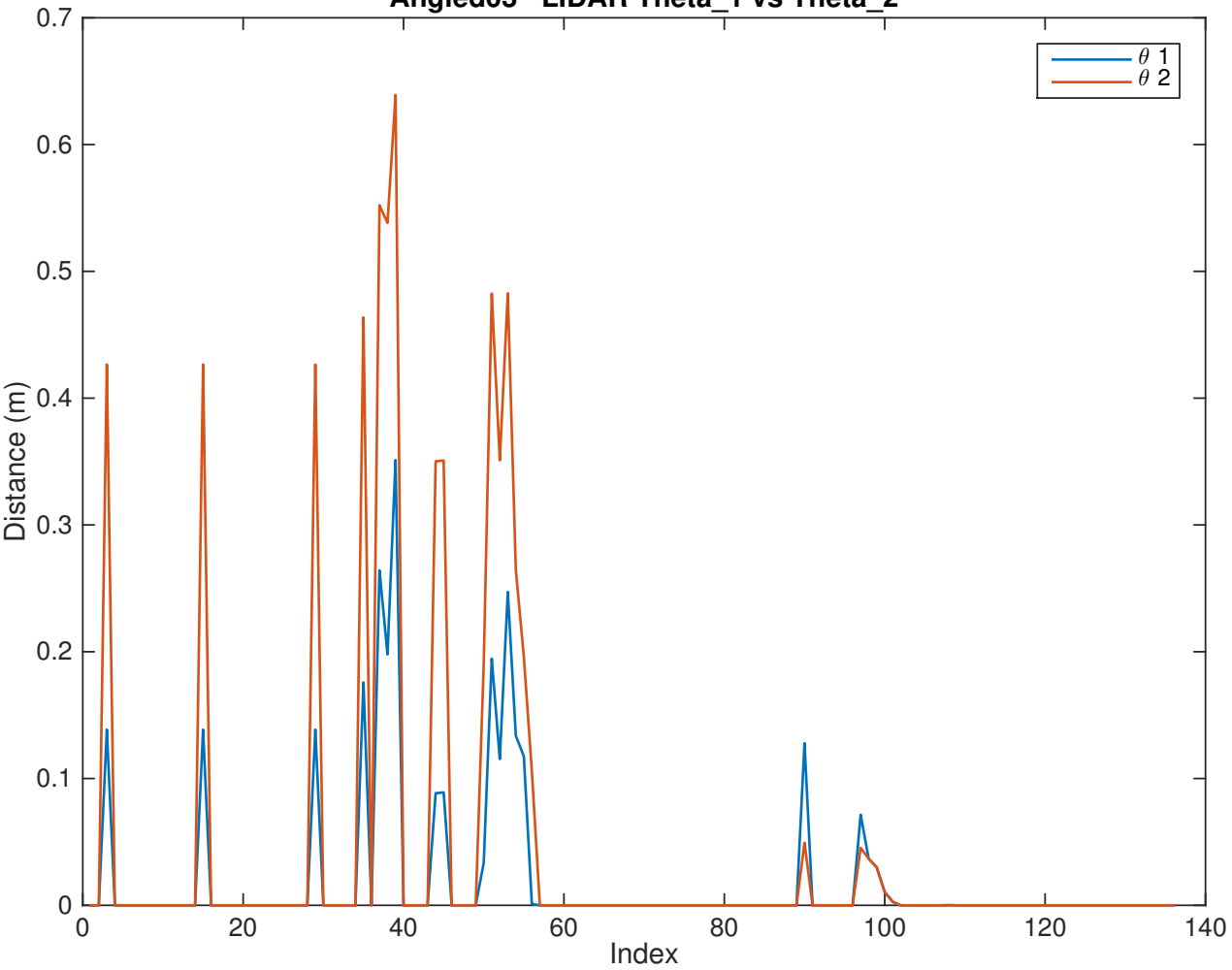
Angled03 Camera L1 vs L2 rolling average



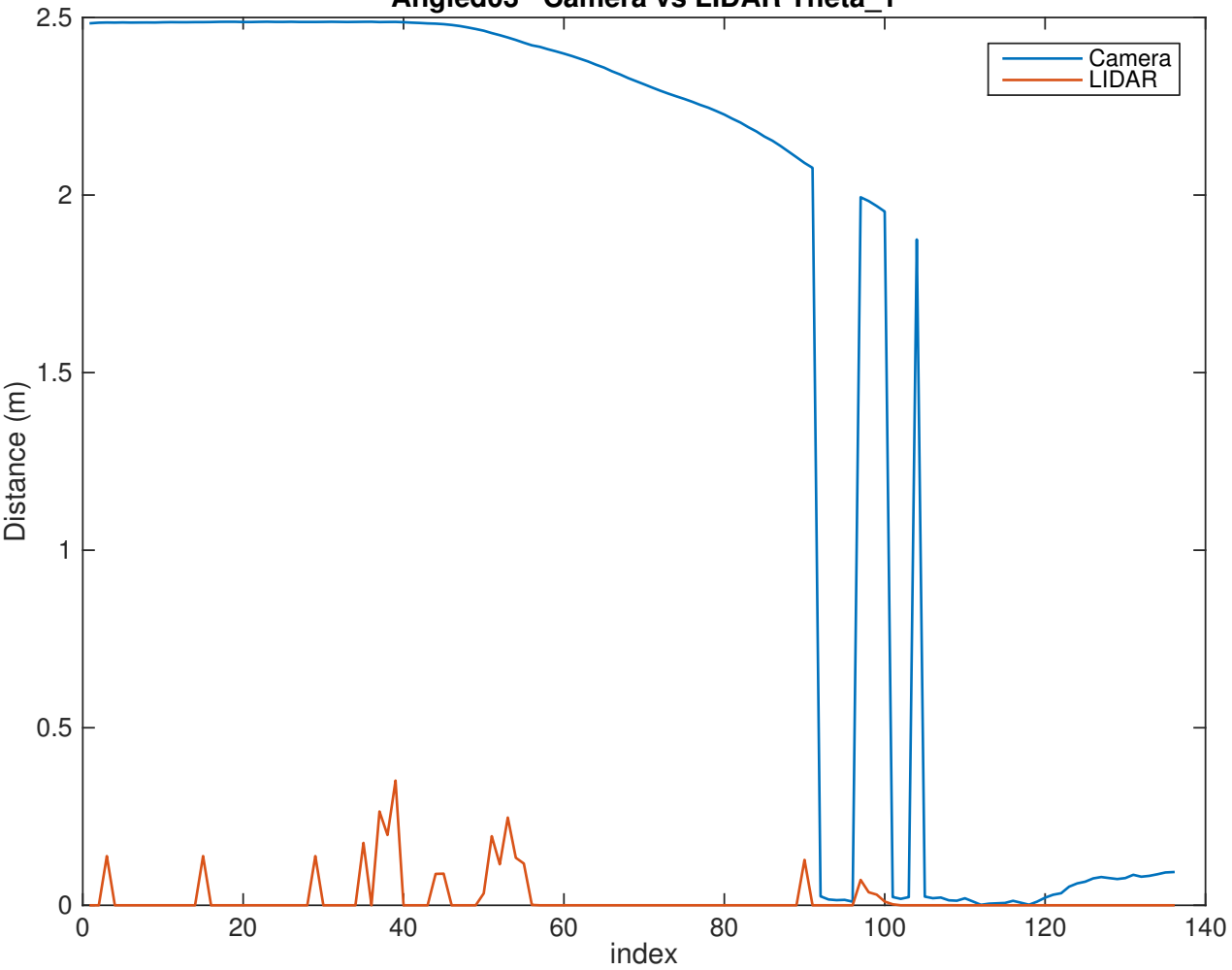
Angled03 Camera Theta_1 vs Theta_2



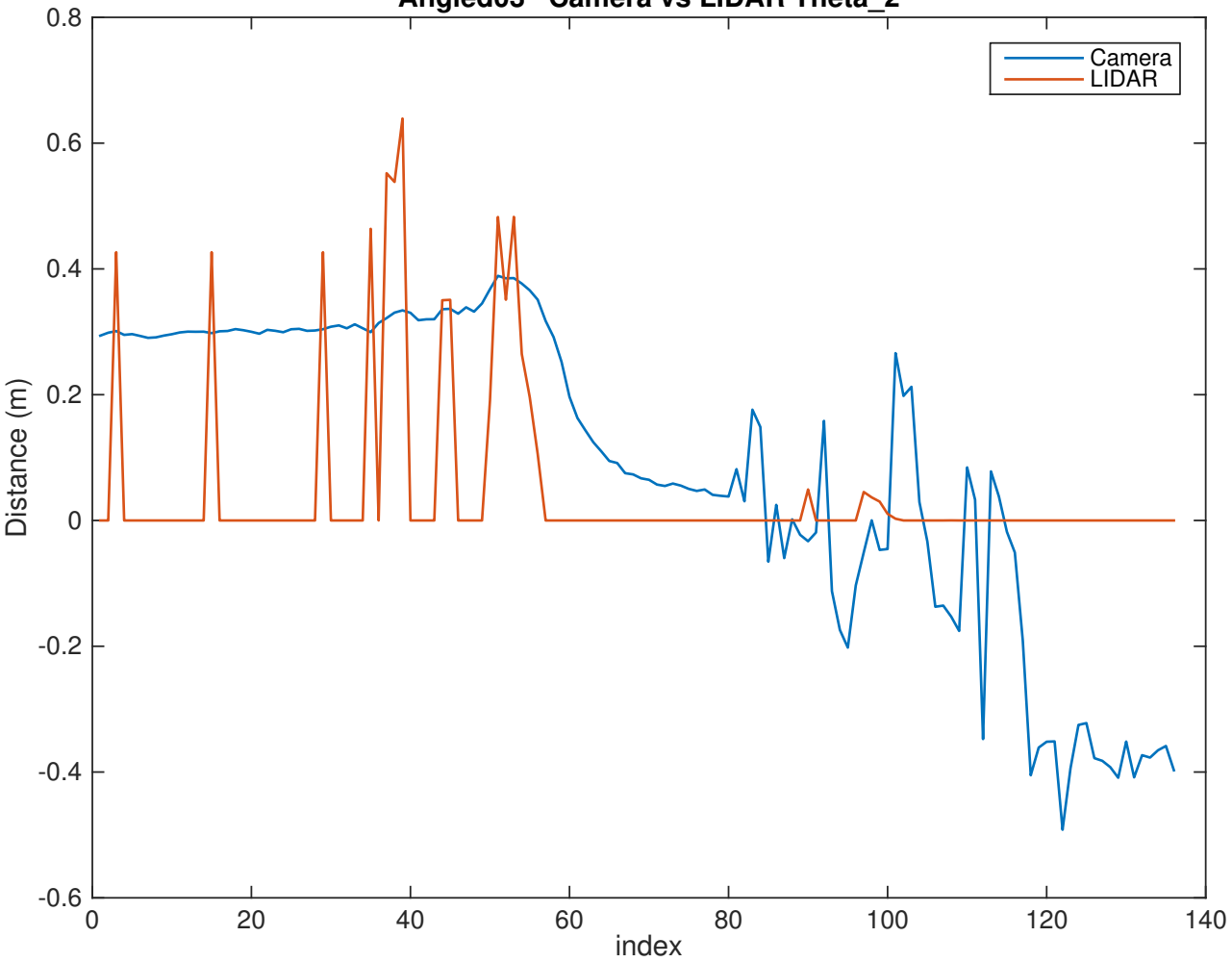
Angled03 LIDAR Theta_1 vs Theta_2



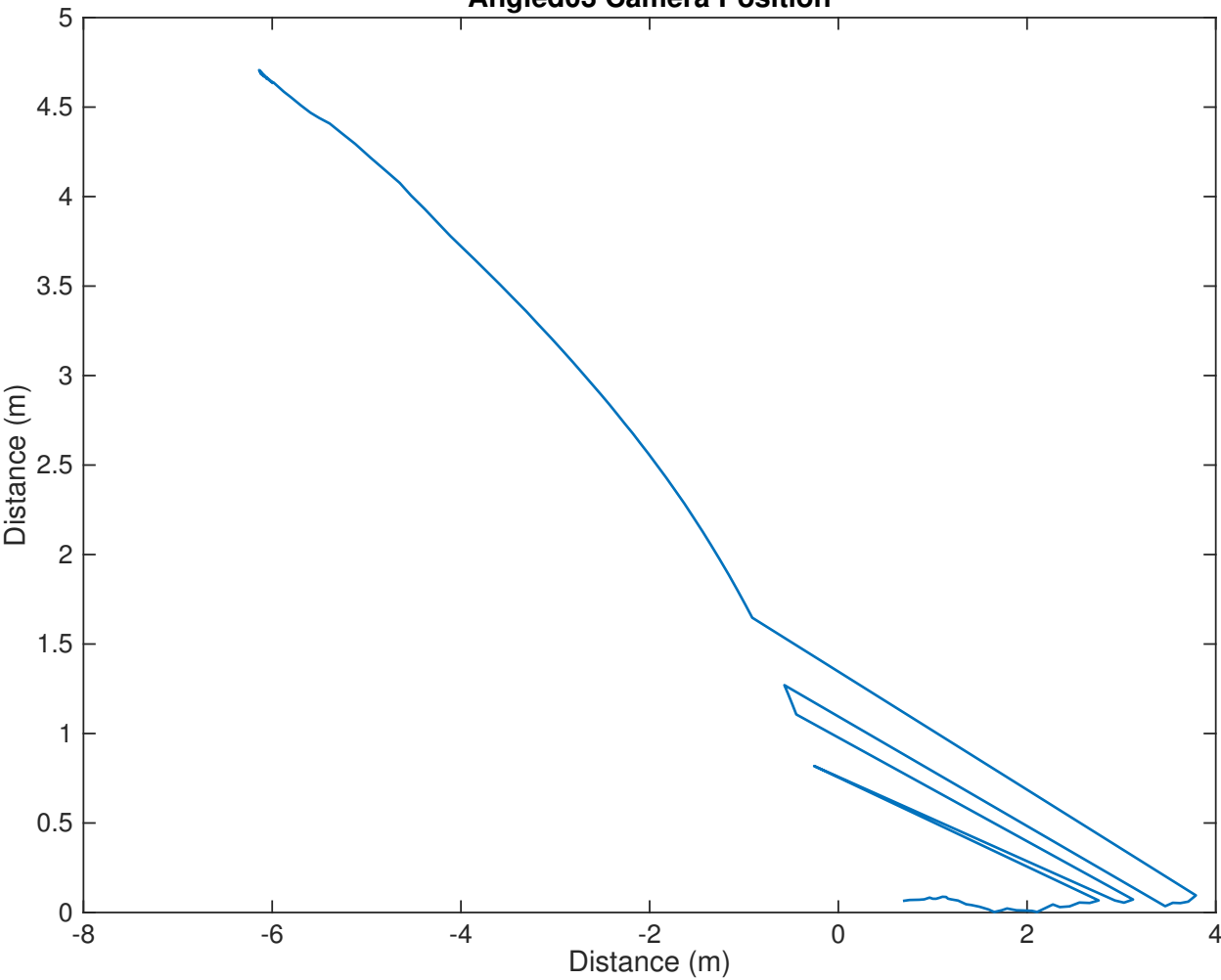
Angled03 Camera vs LIDAR Theta_1



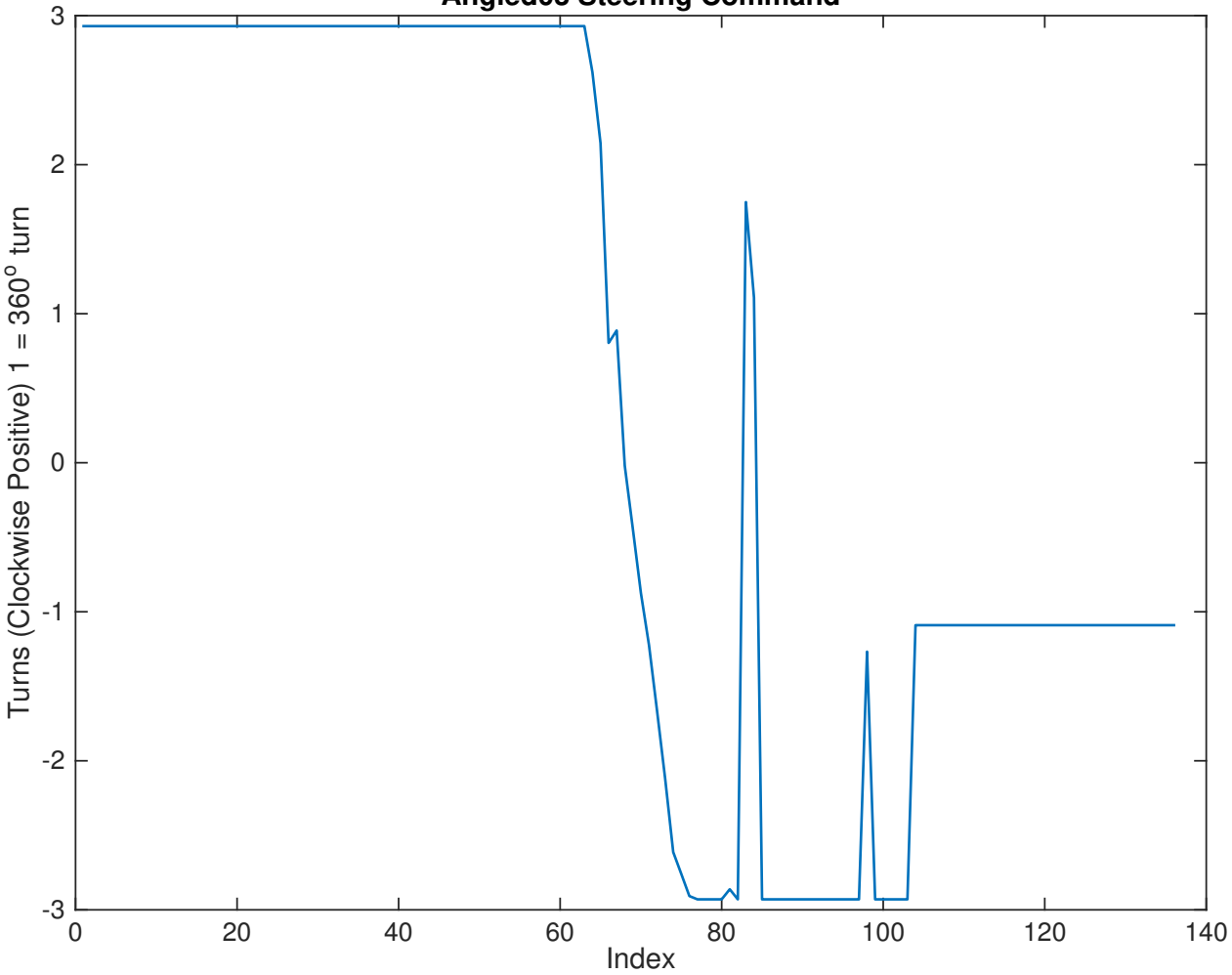
Angled03 Camera vs LIDAR Theta_2



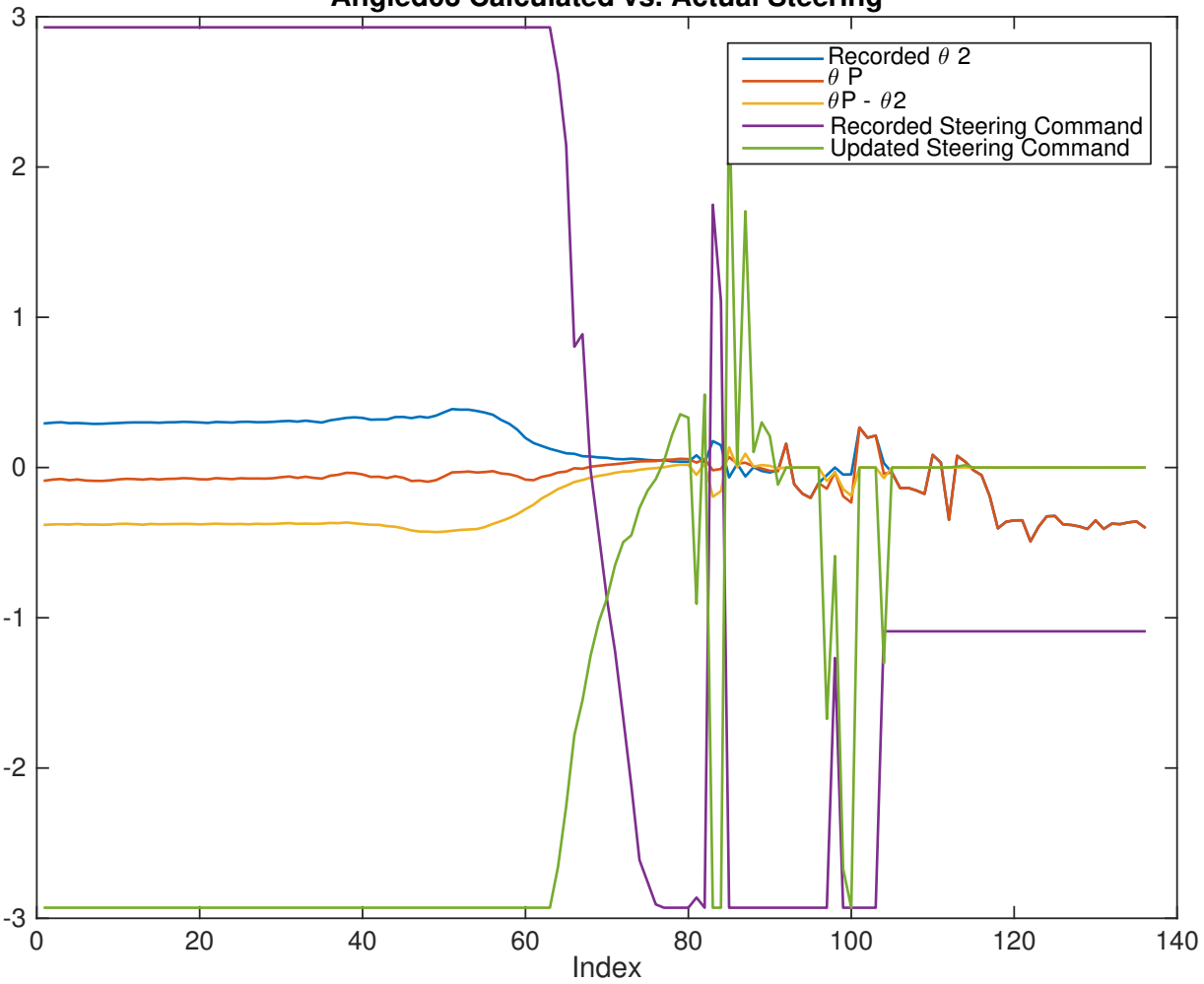
Angled03 Camera Position



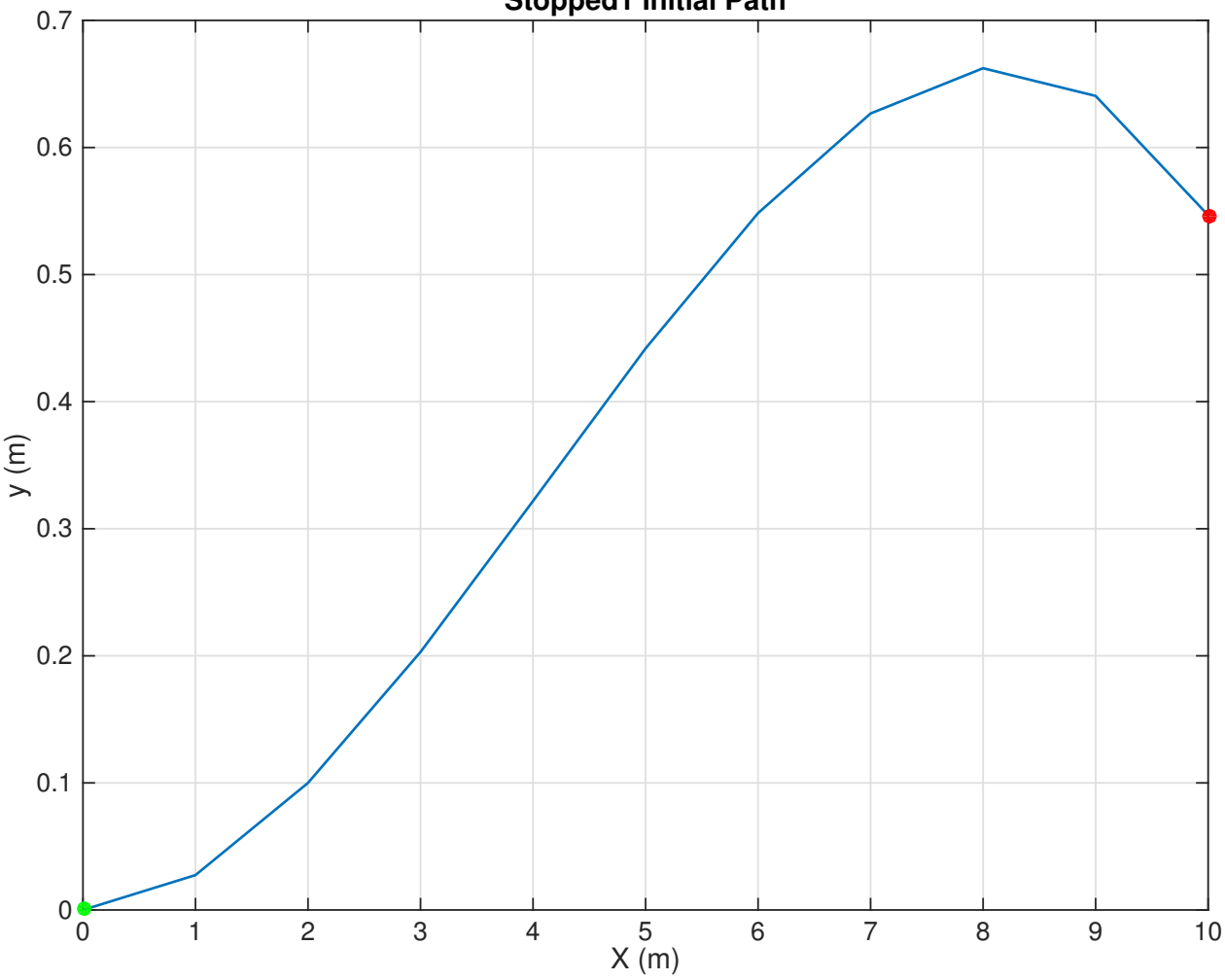
Angled03 Steering Command



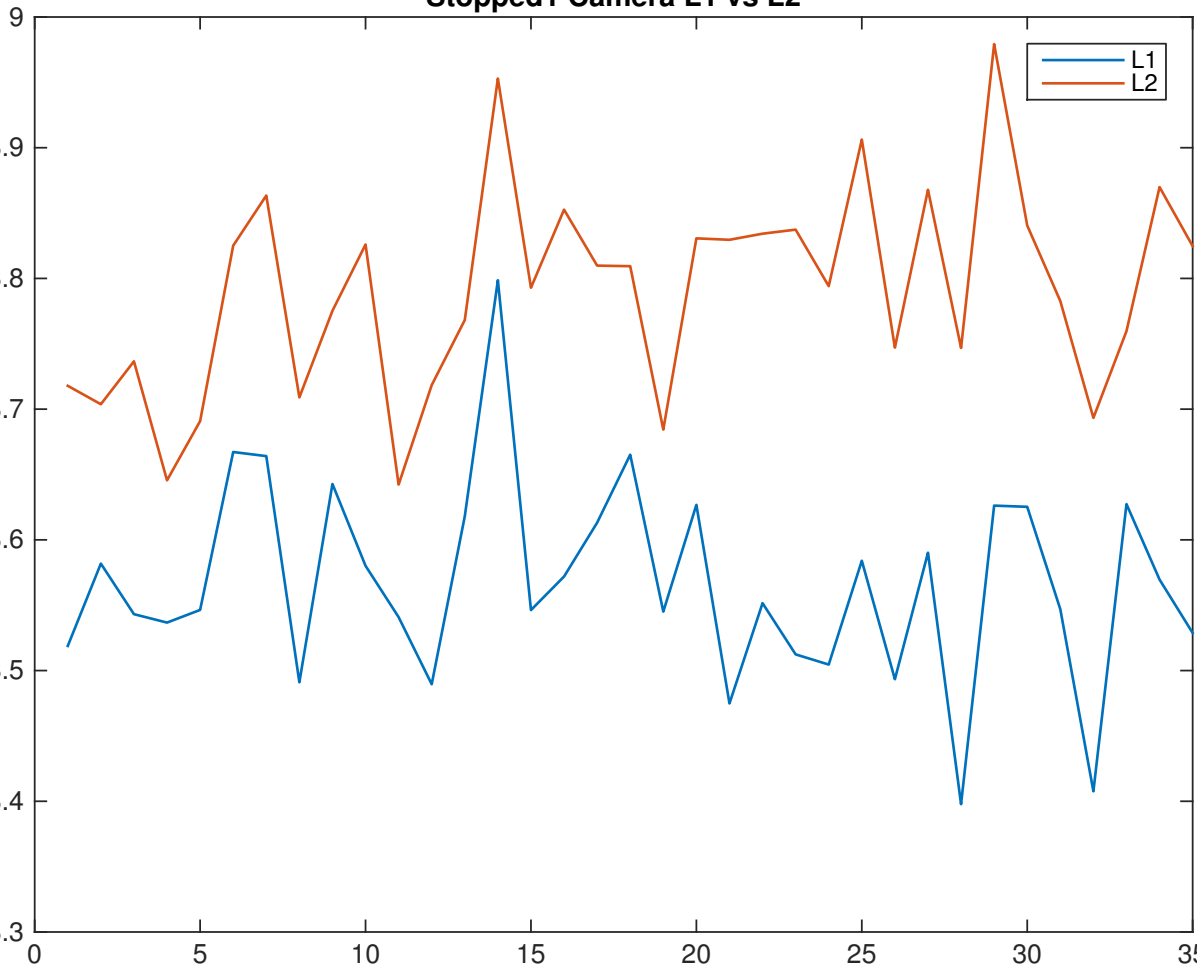
Angled03 Calculated vs. Actual Steering



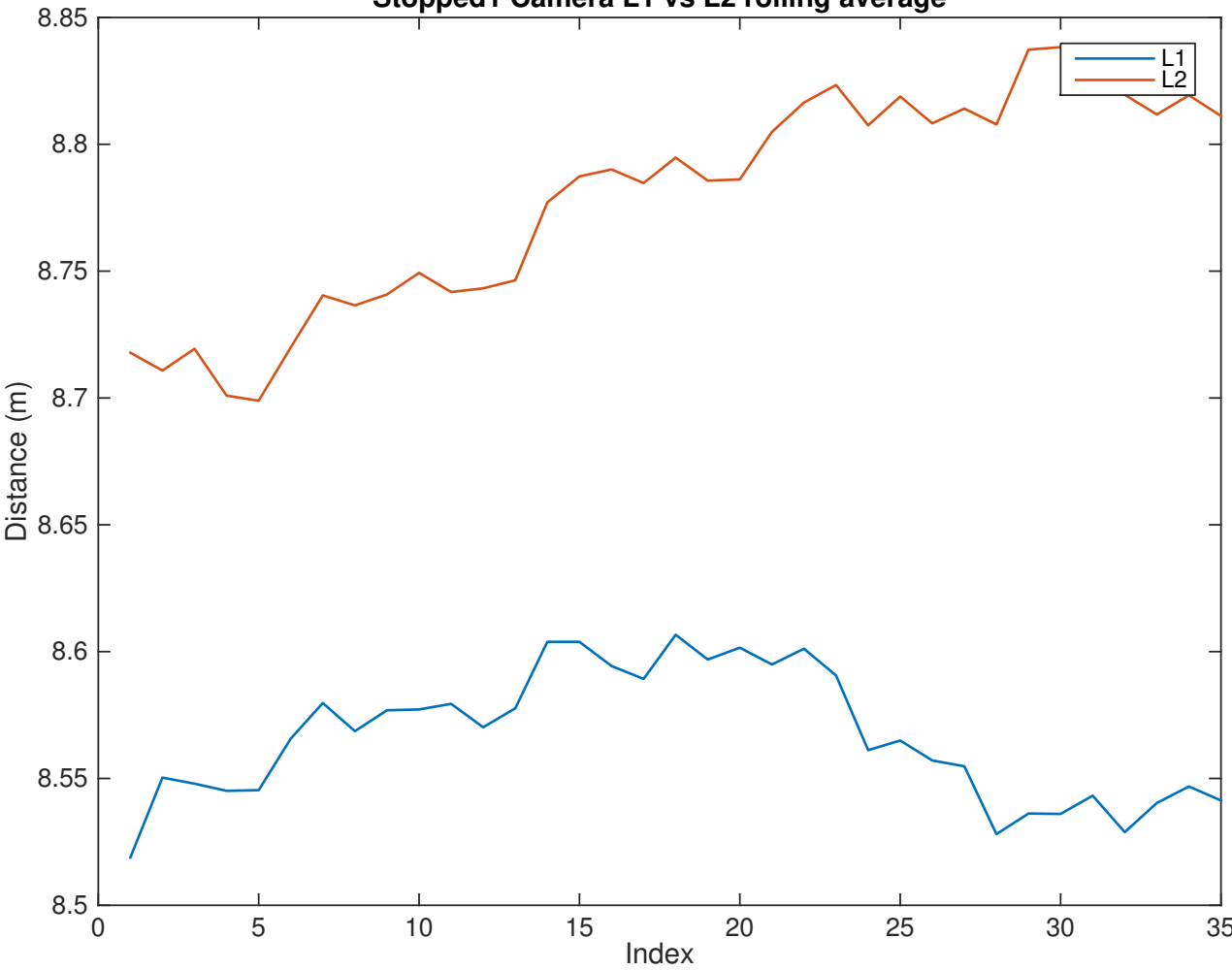
Stopped1 Initial Path



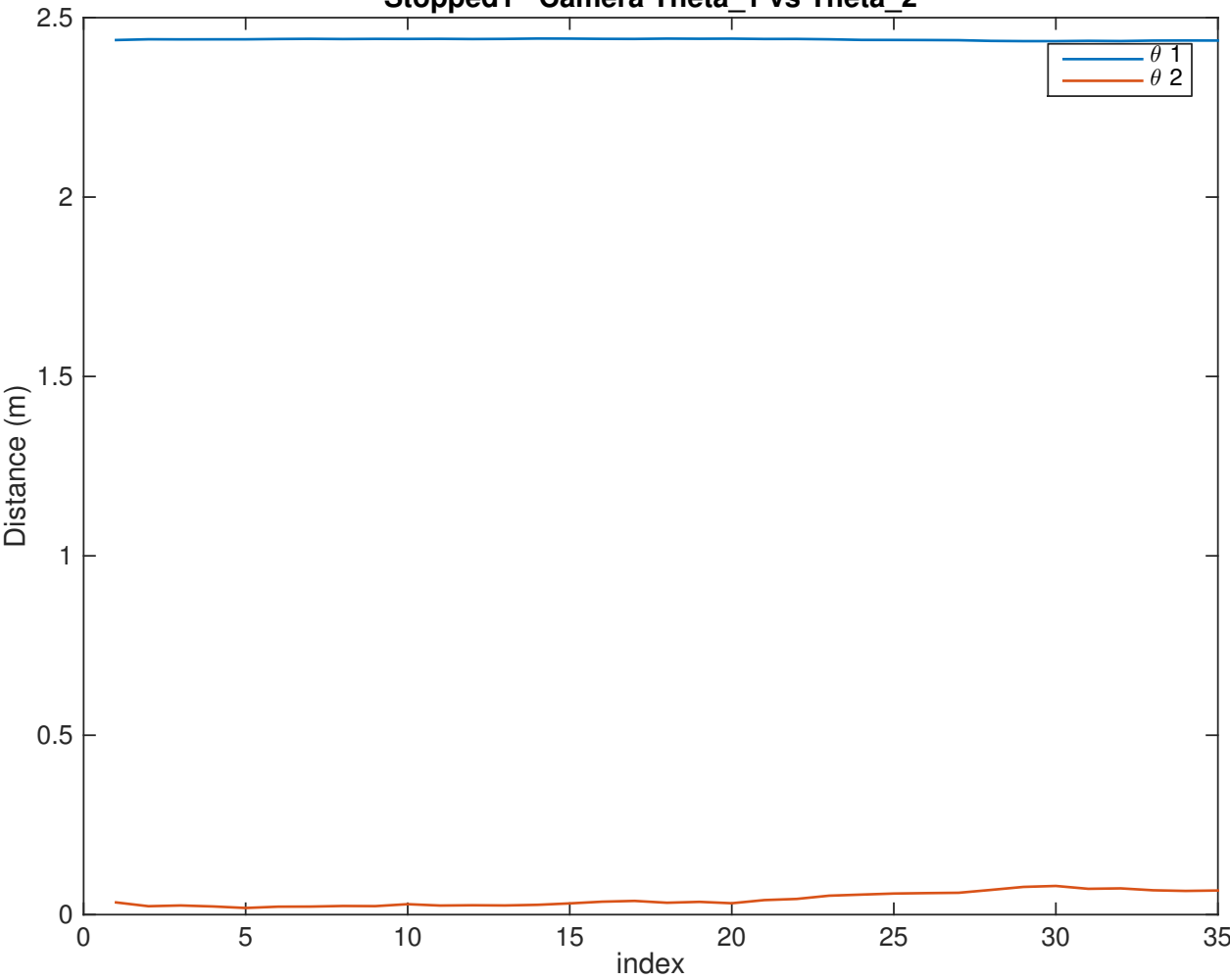
Stopped1 Camera L1 vs L2



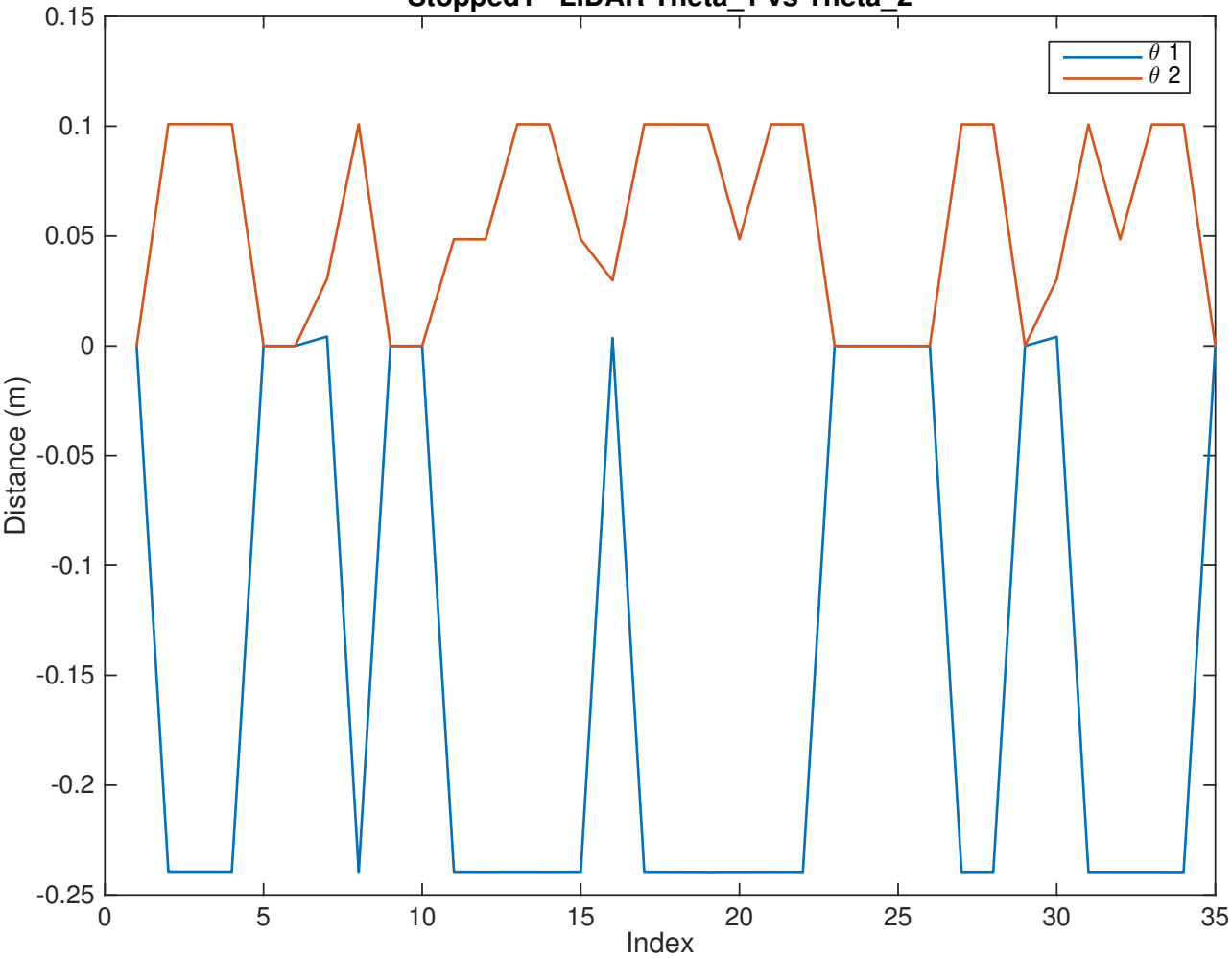
Stopped1 Camera L1 vs L2 rolling average



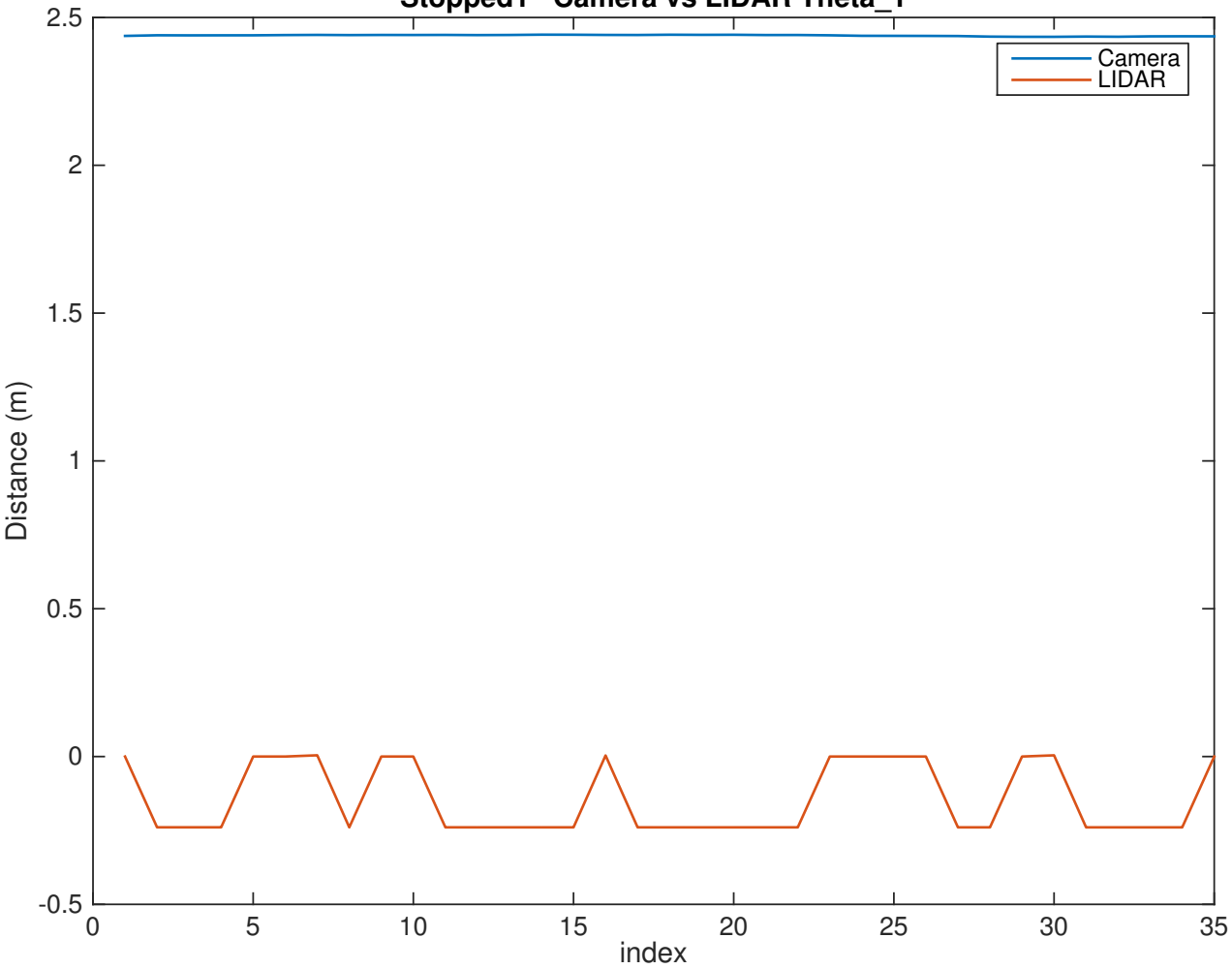
Stopped1 Camera Theta_1 vs Theta_2



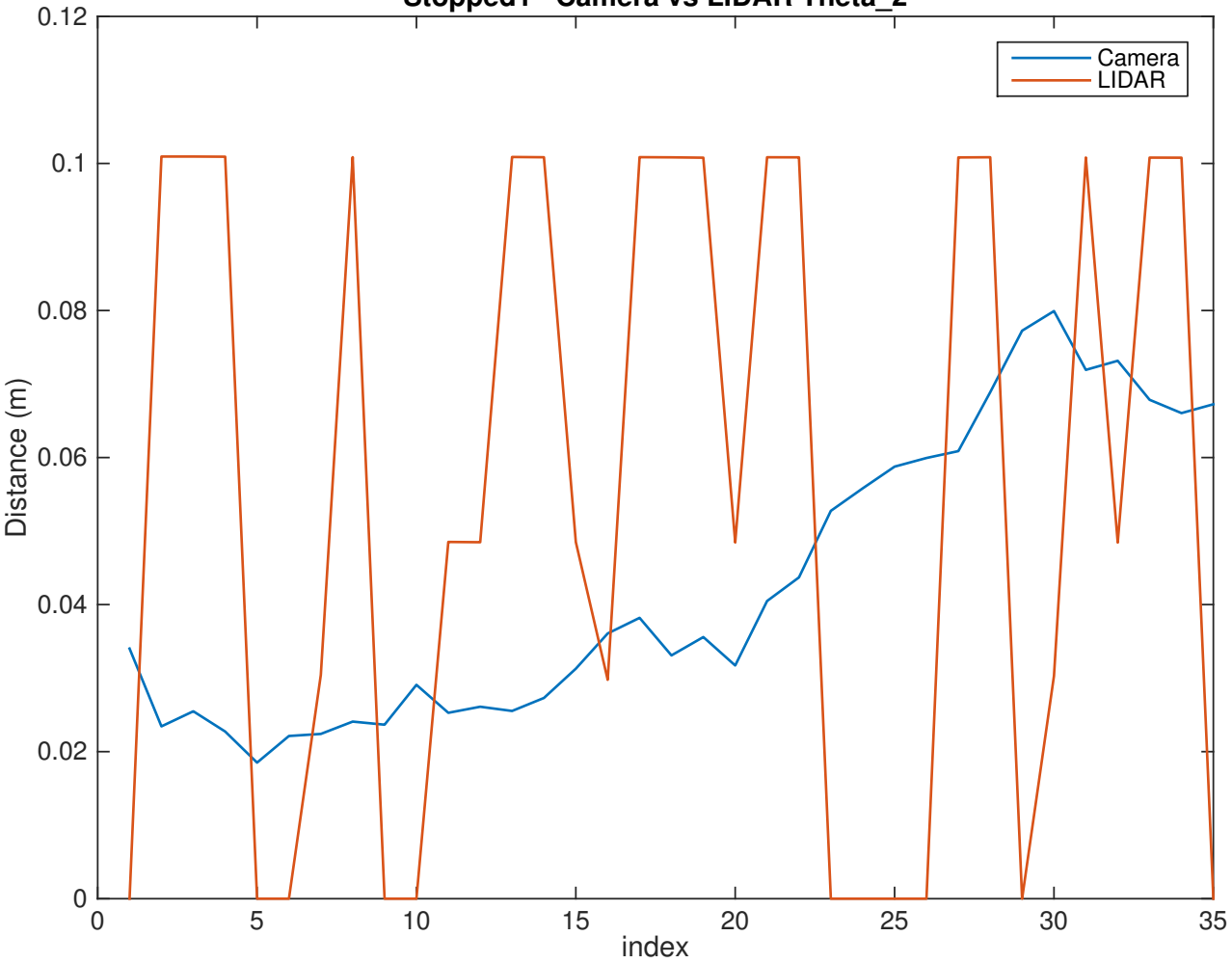
Stopped1 LIDAR Theta_1 vs Theta_2



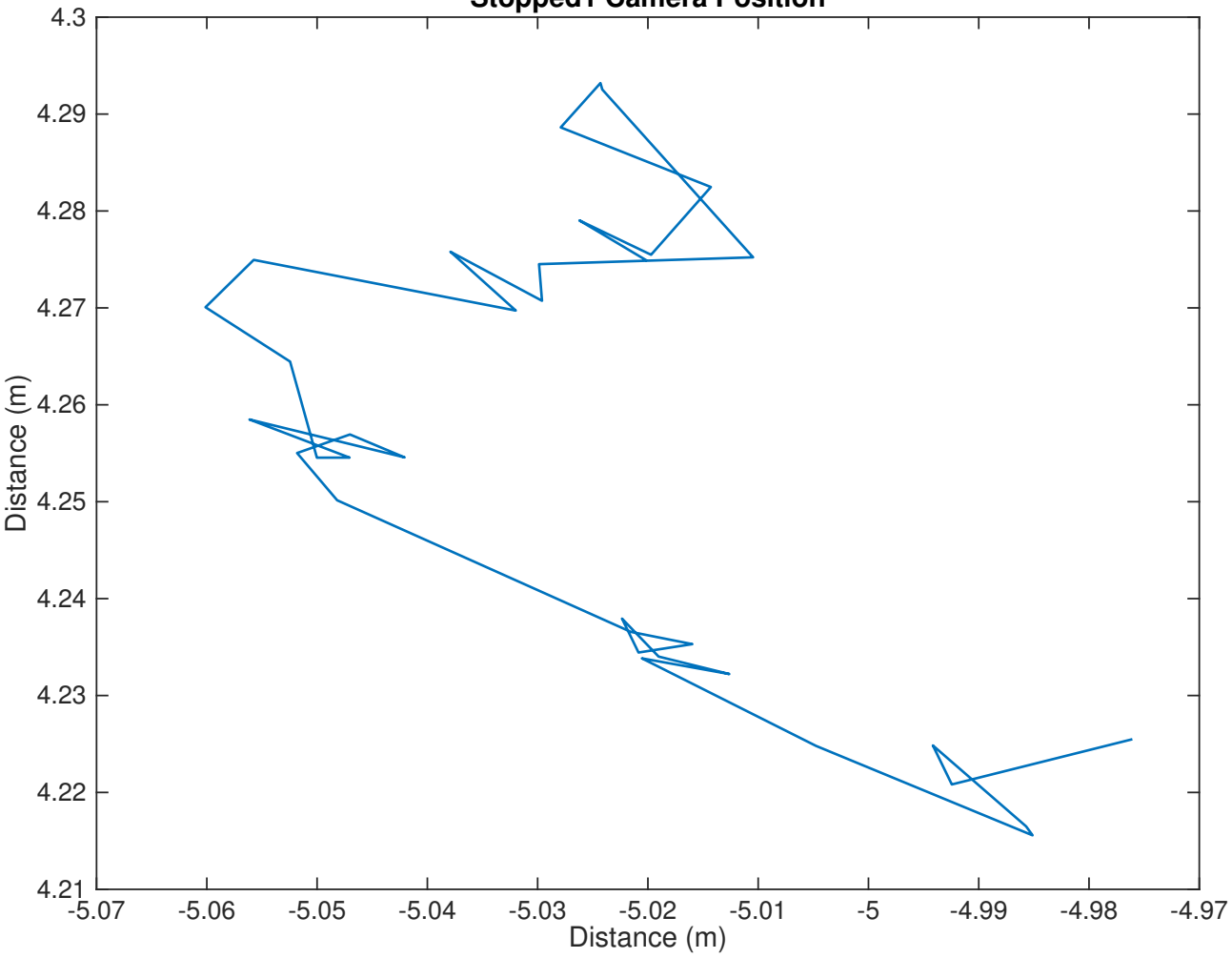
Stopped1 Camera vs LIDAR Theta_1



Stopped1 Camera vs LIDAR Theta_2

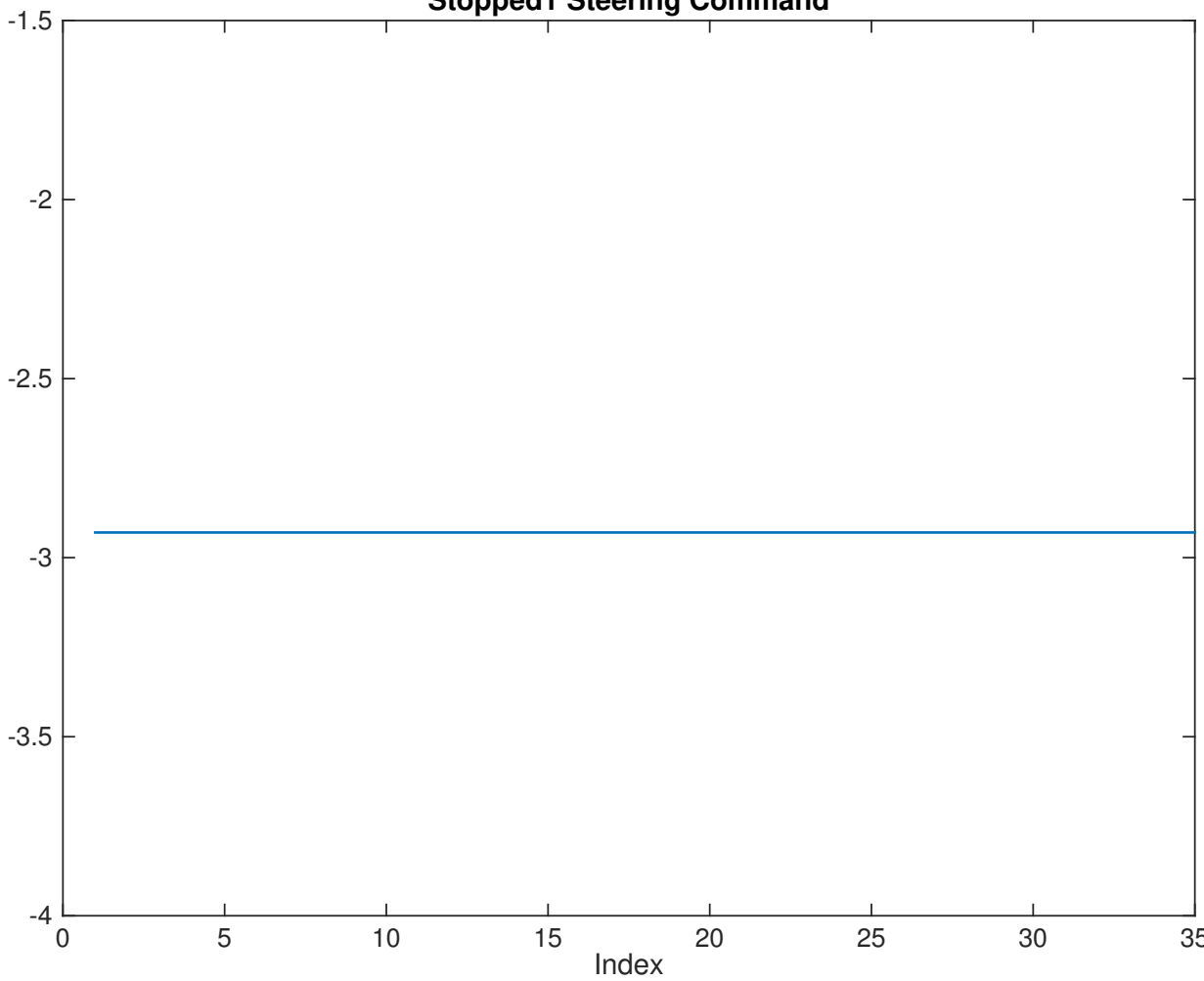


Stopped1 Camera Position

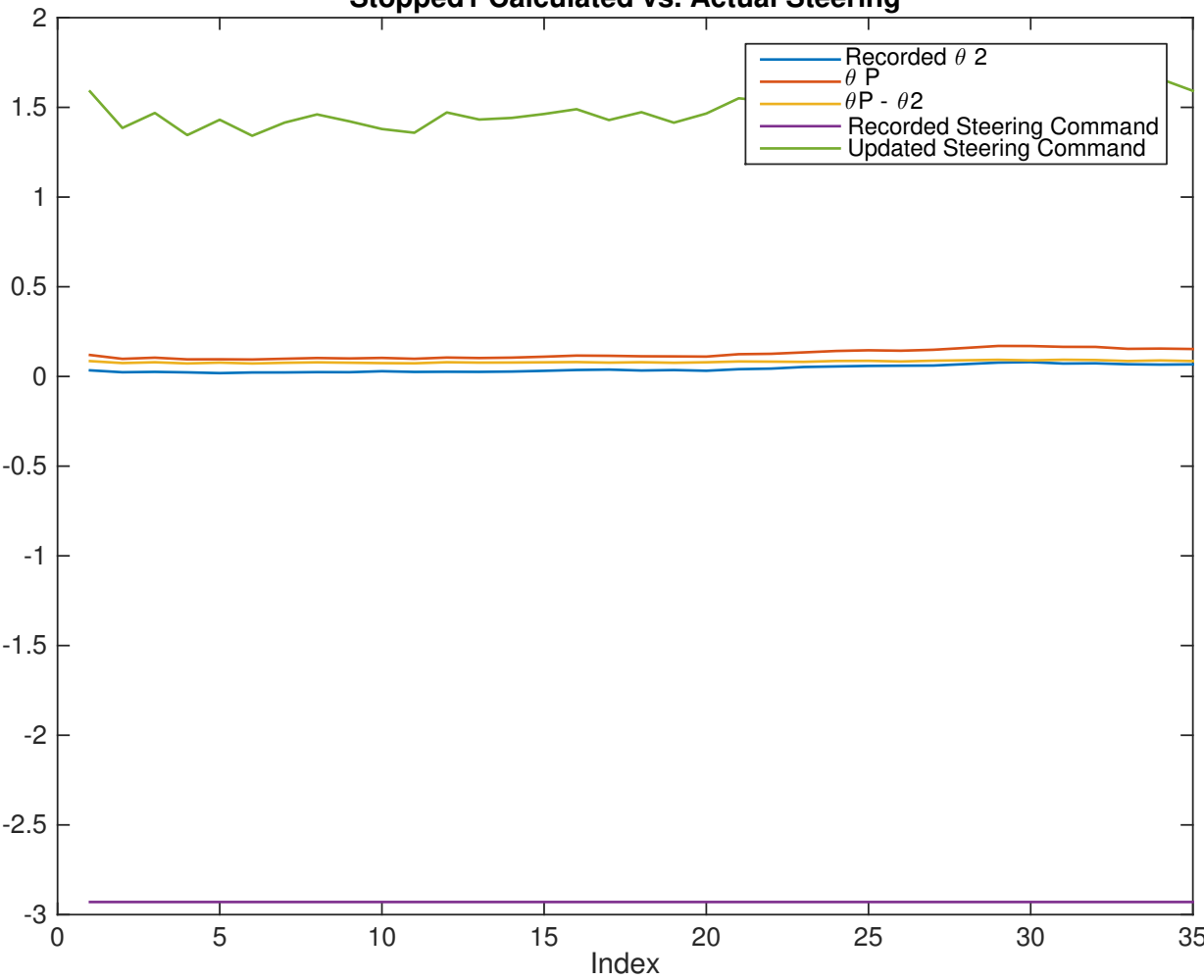


Stopped1 Steering Command

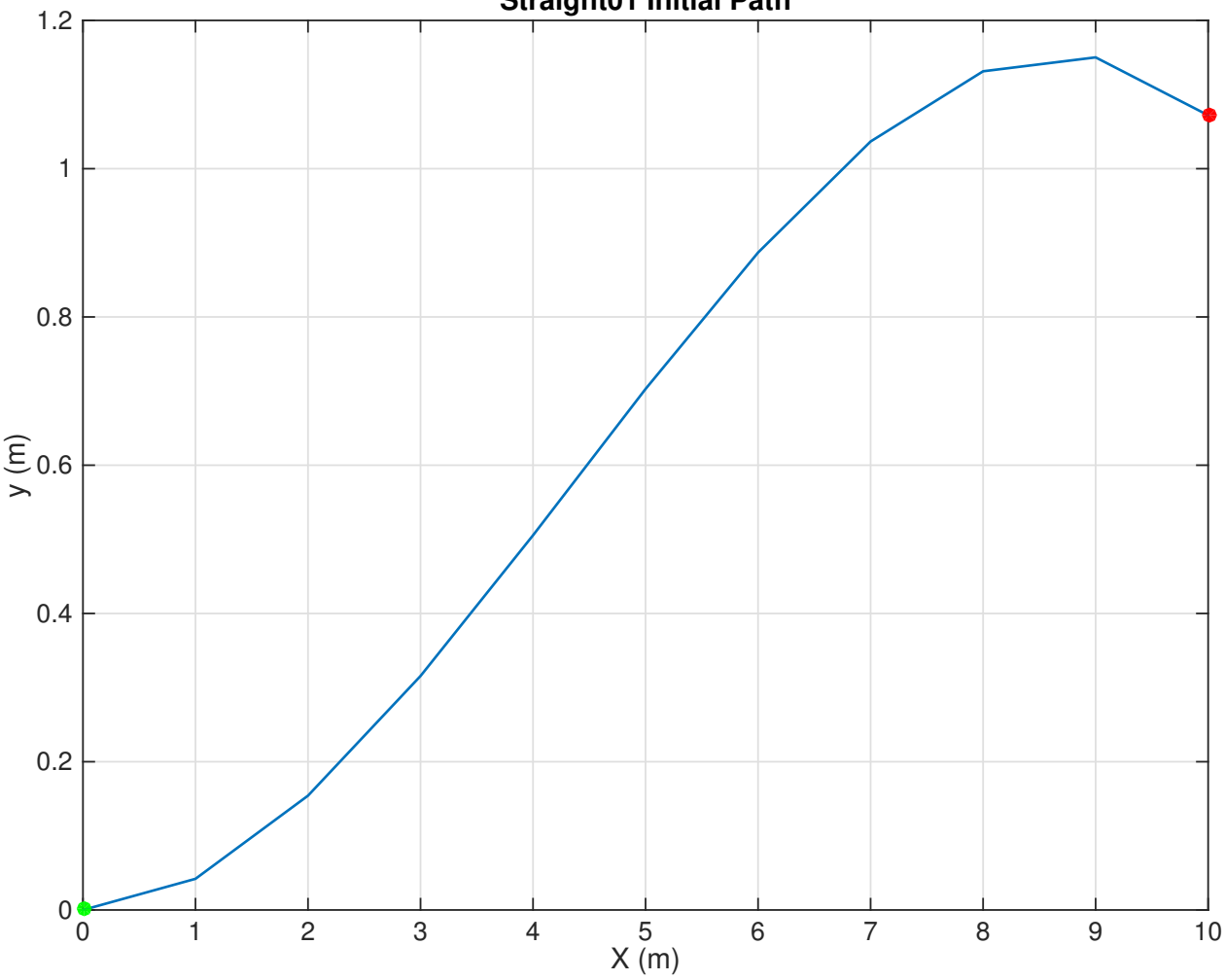
Turns (Clockwise Positive) 1 = 360° turn



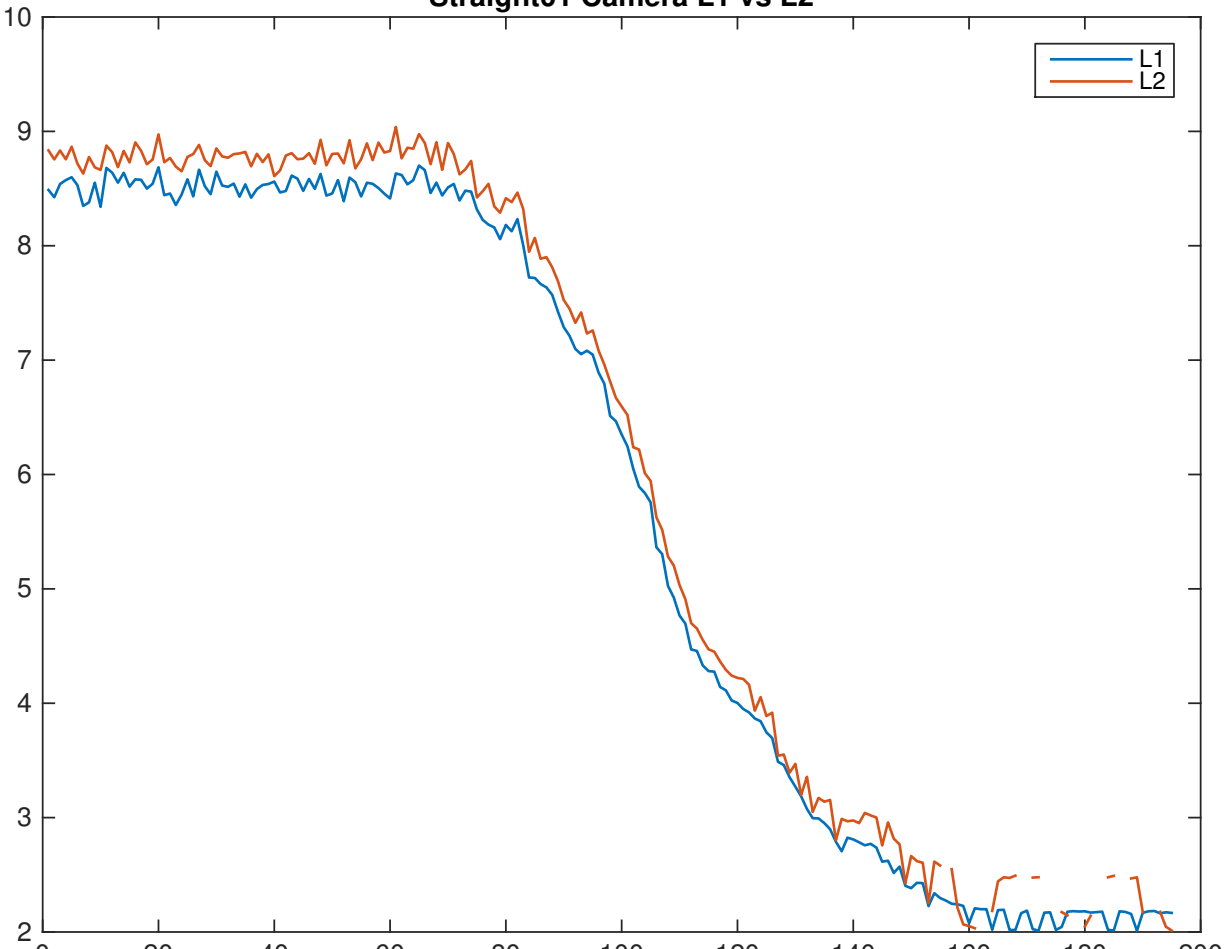
Stopped1 Calculated vs. Actual Steering



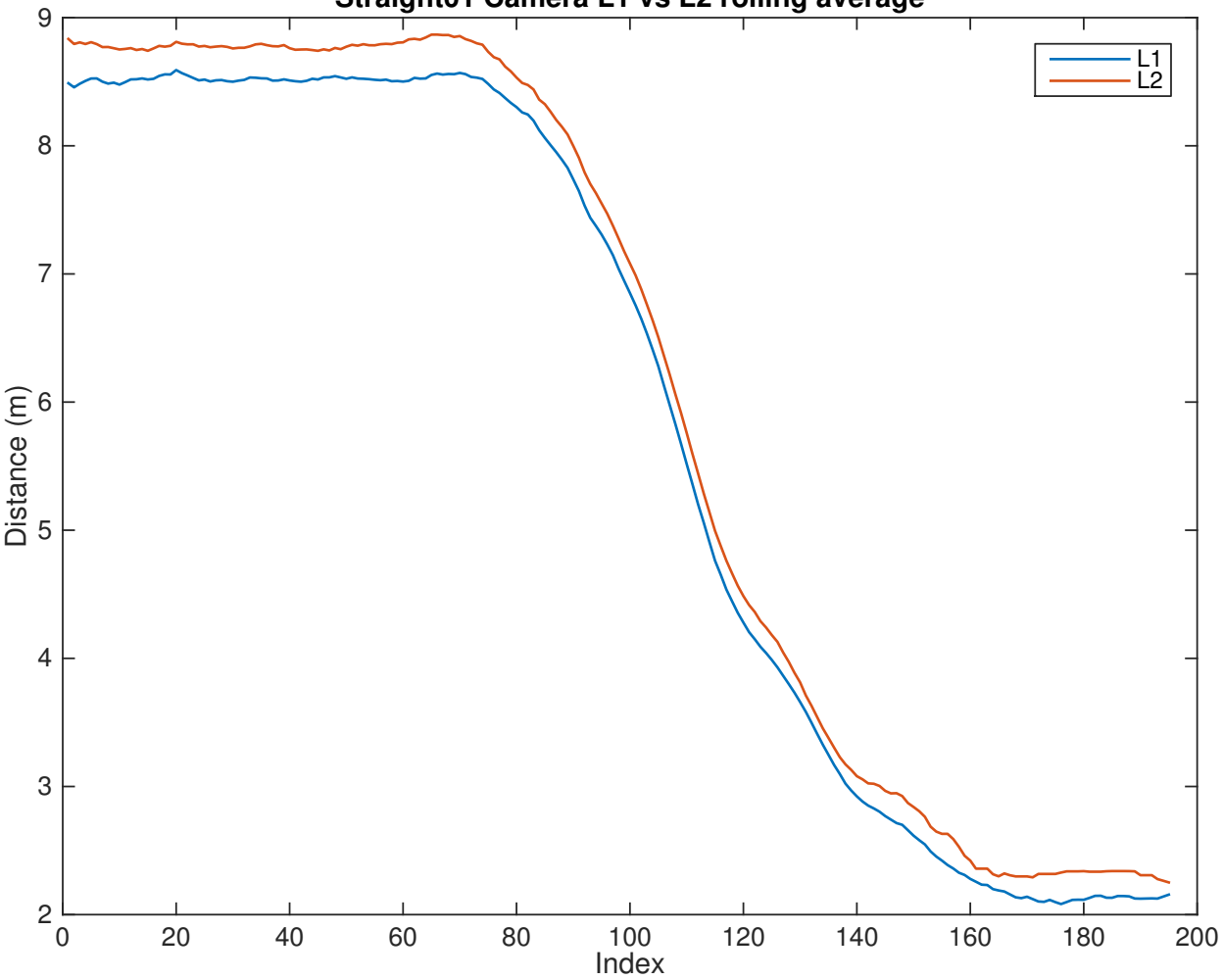
Straight01 Initial Path



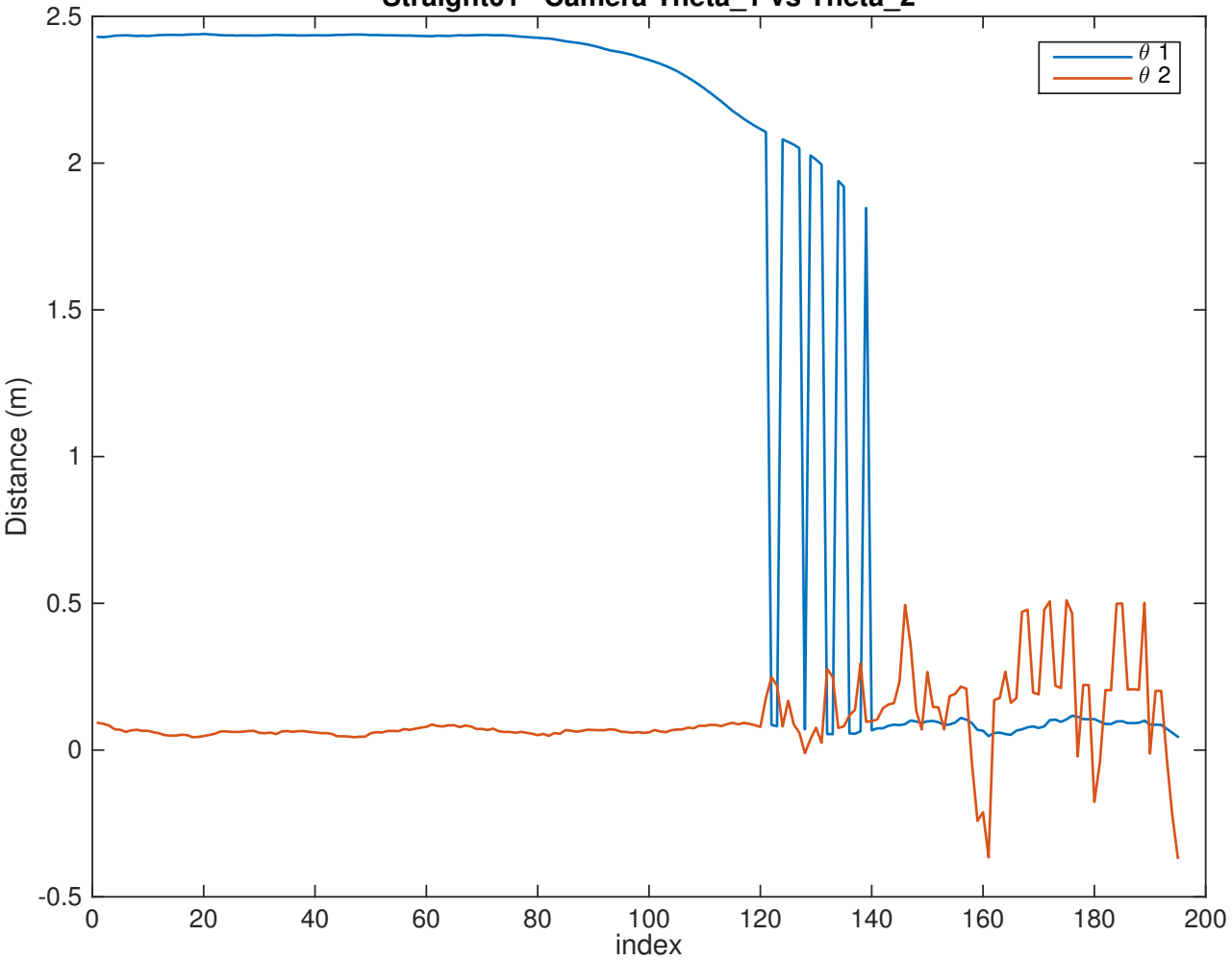
Straight01 Camera L1 vs L2



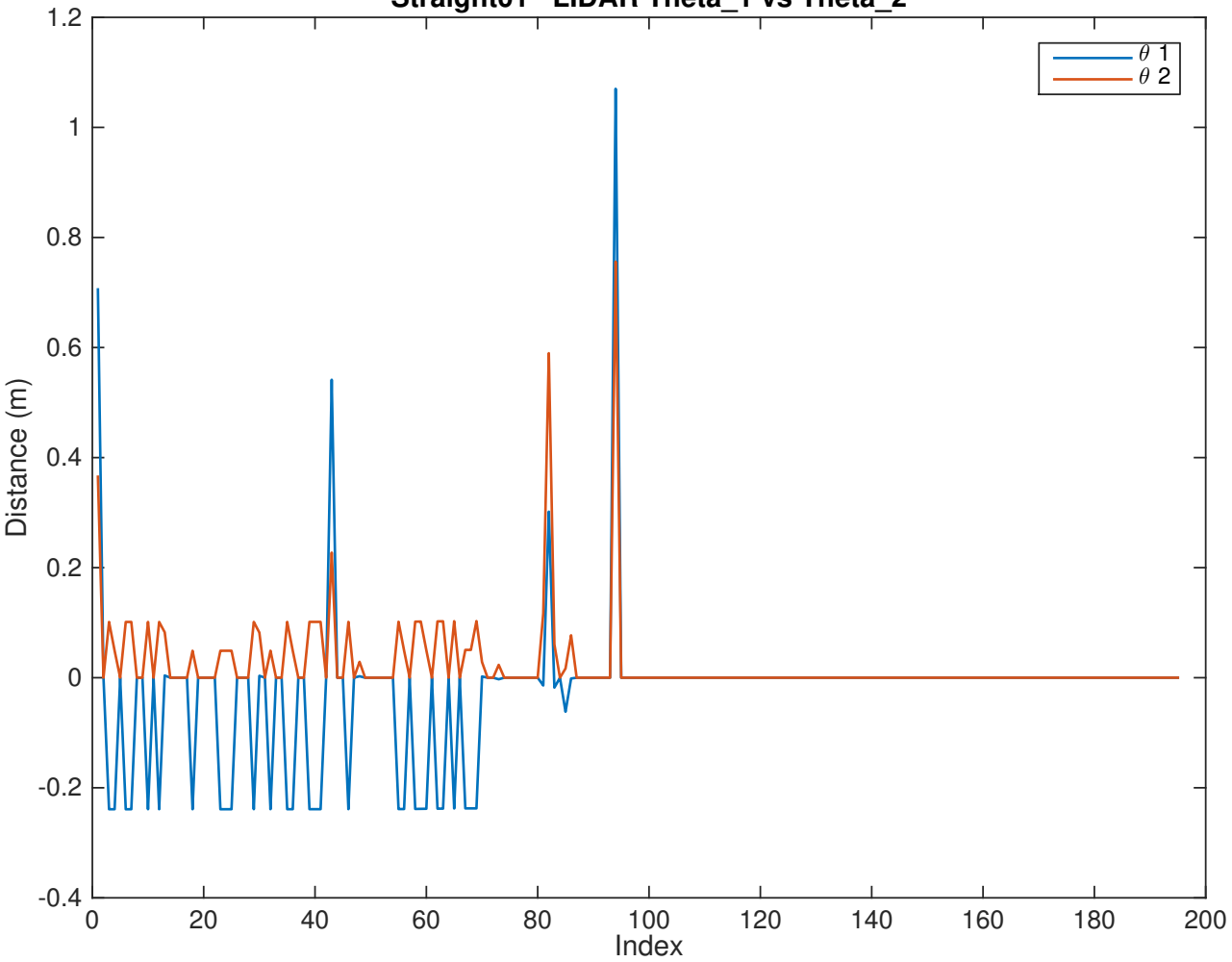
Straight01 Camera L1 vs L2 rolling average



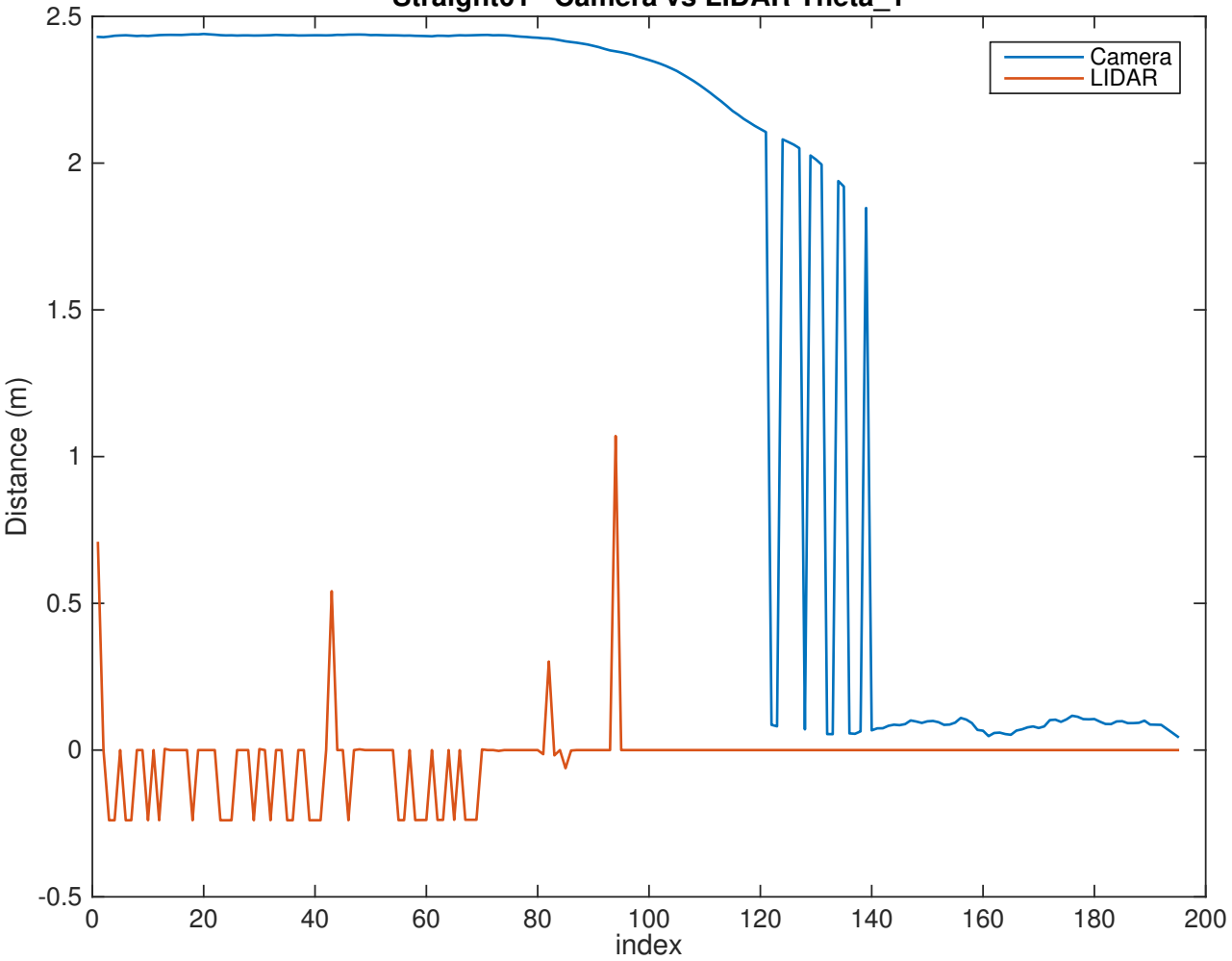
Straight01 Camera Theta_1 vs Theta_2



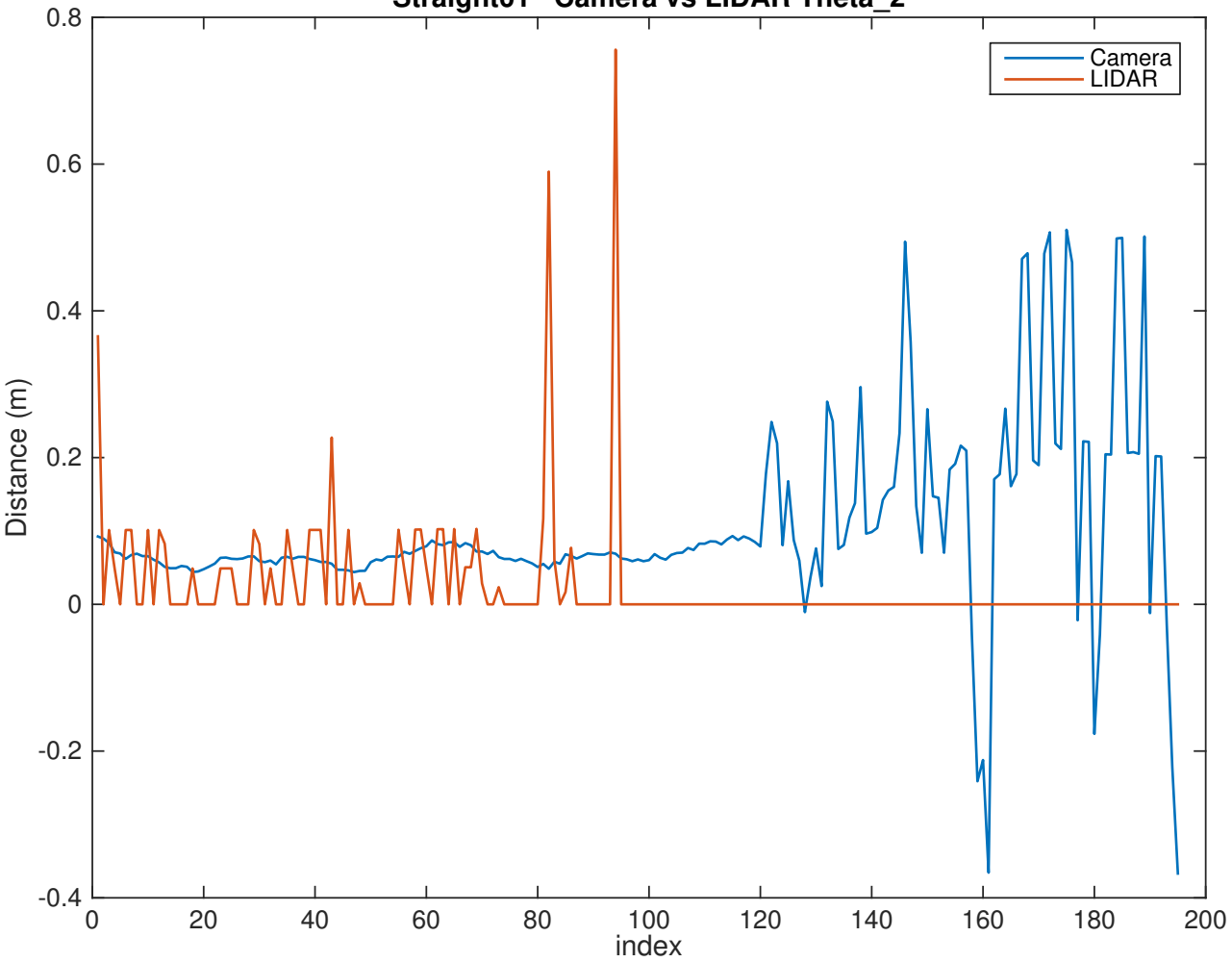
Straight01 LIDAR Theta_1 vs Theta_2



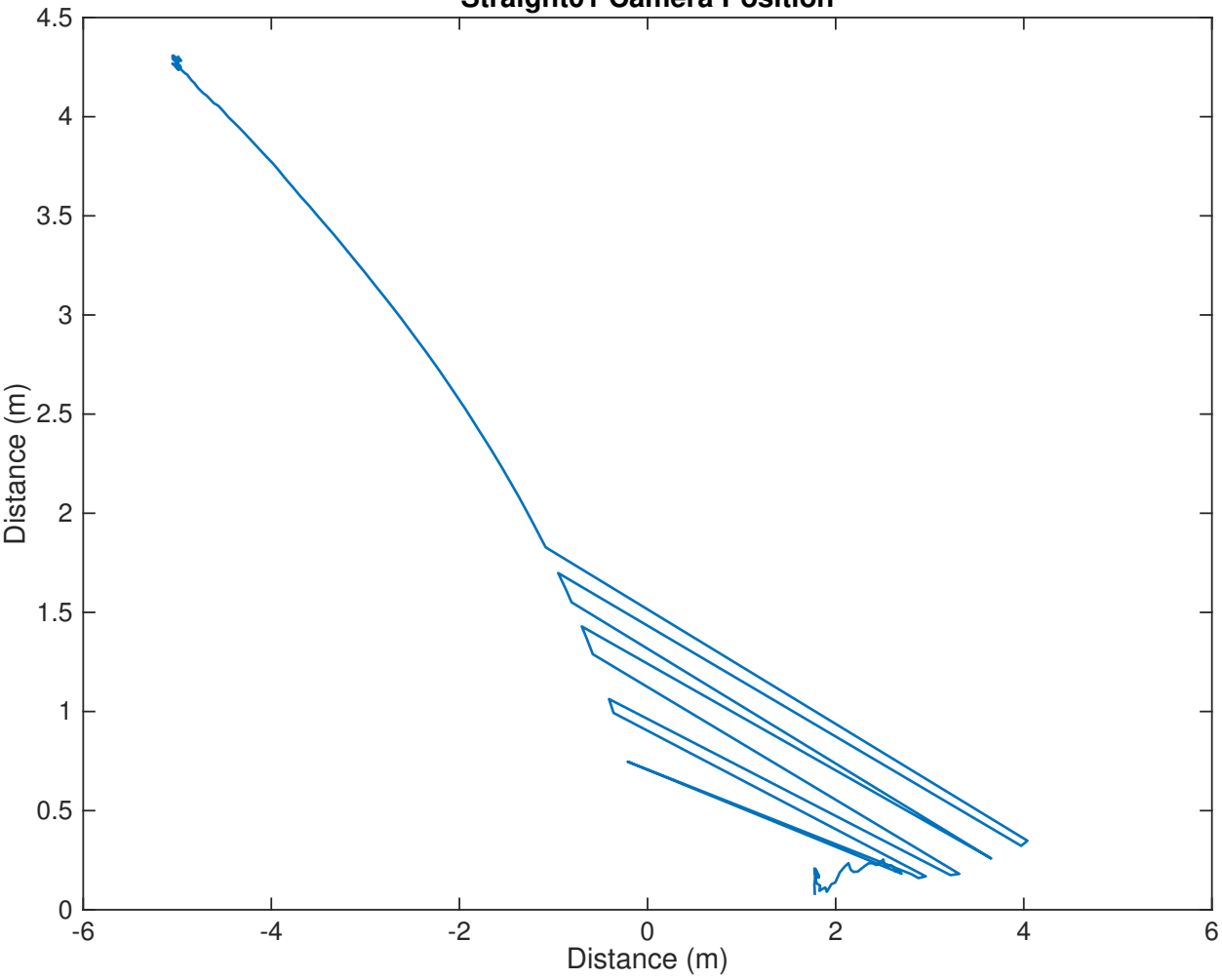
Straight01 Camera vs LIDAR Theta_1



Straight01 Camera vs LIDAR Theta_2

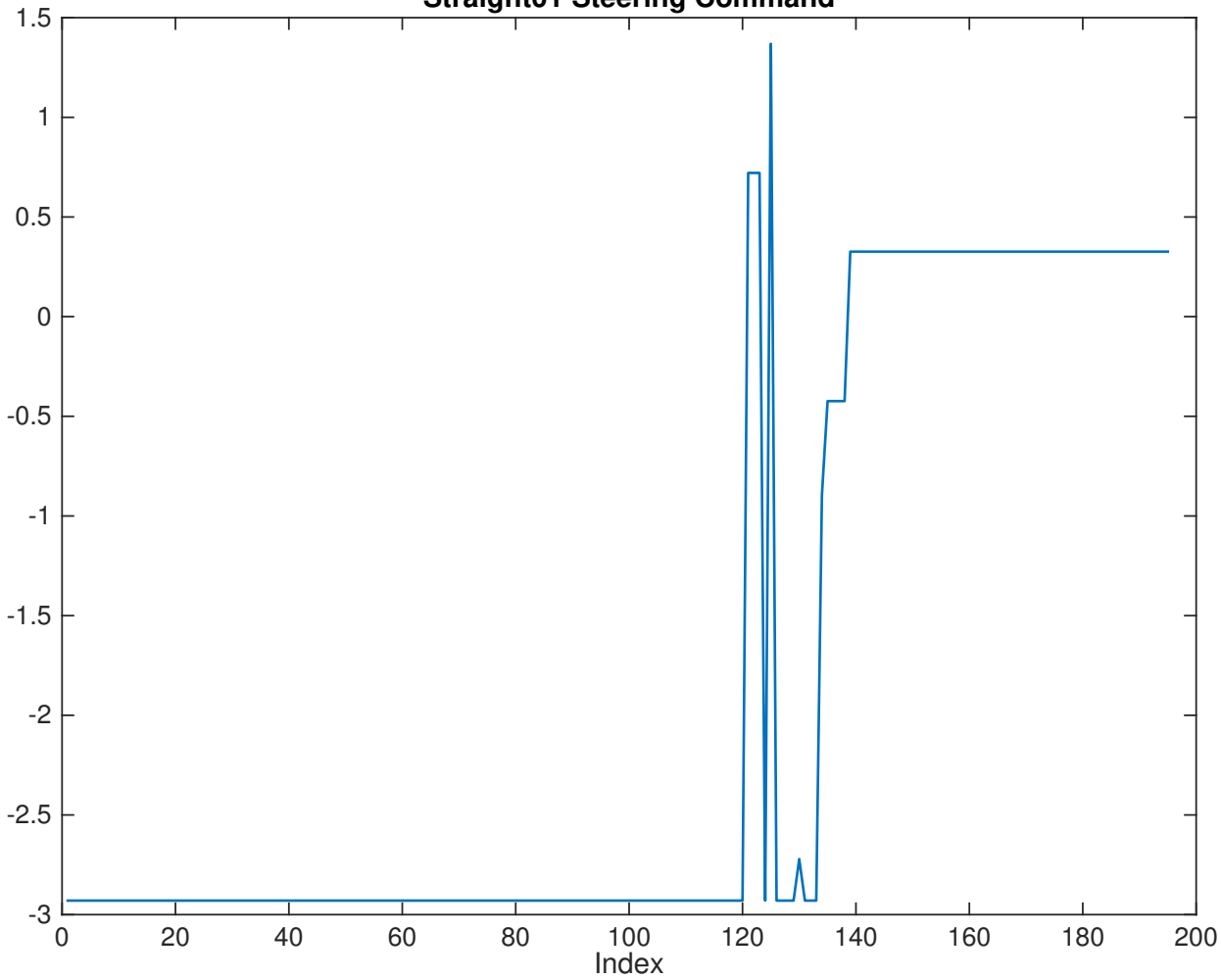


Straight01 Camera Position

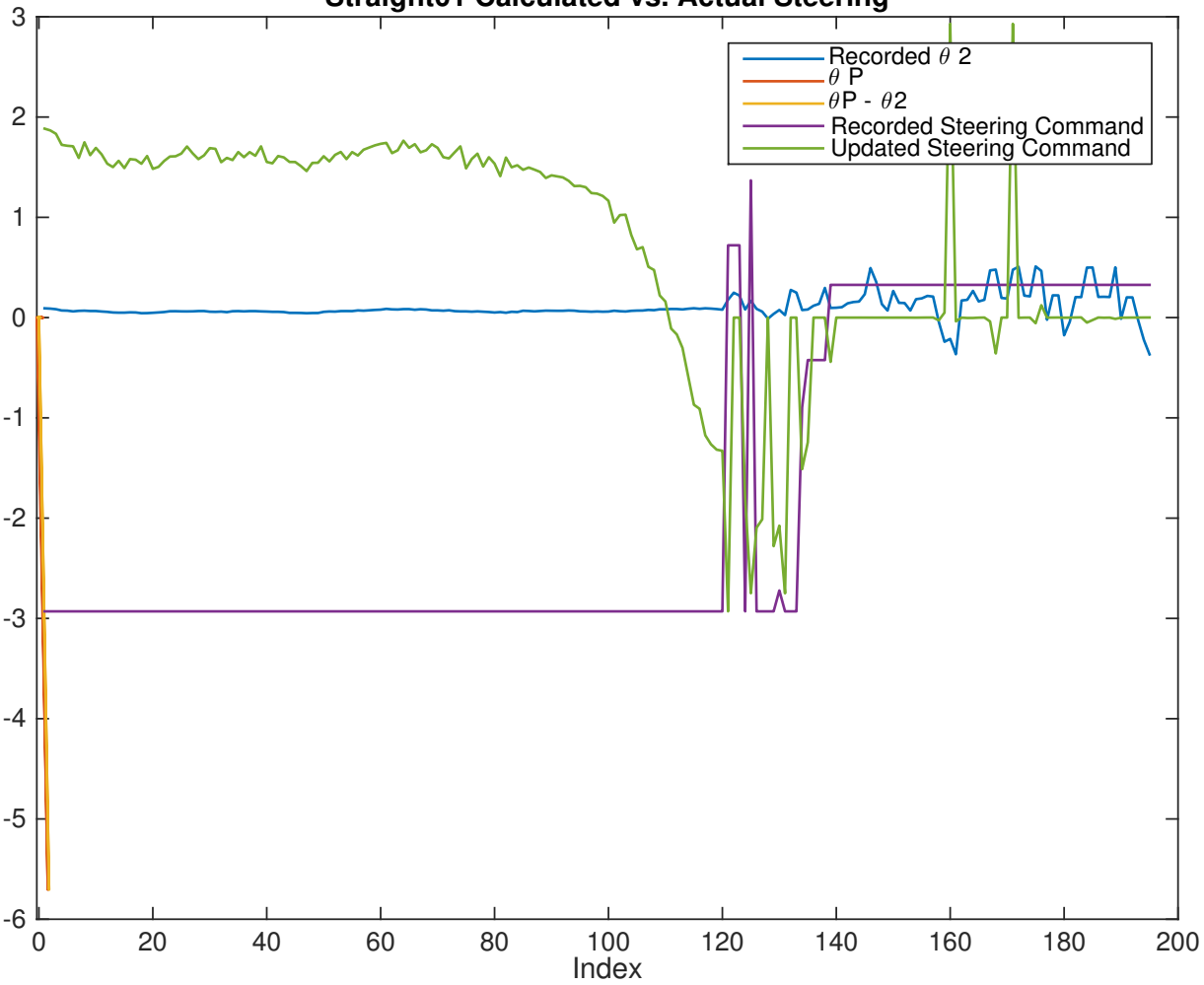


Straight01 Steering Command

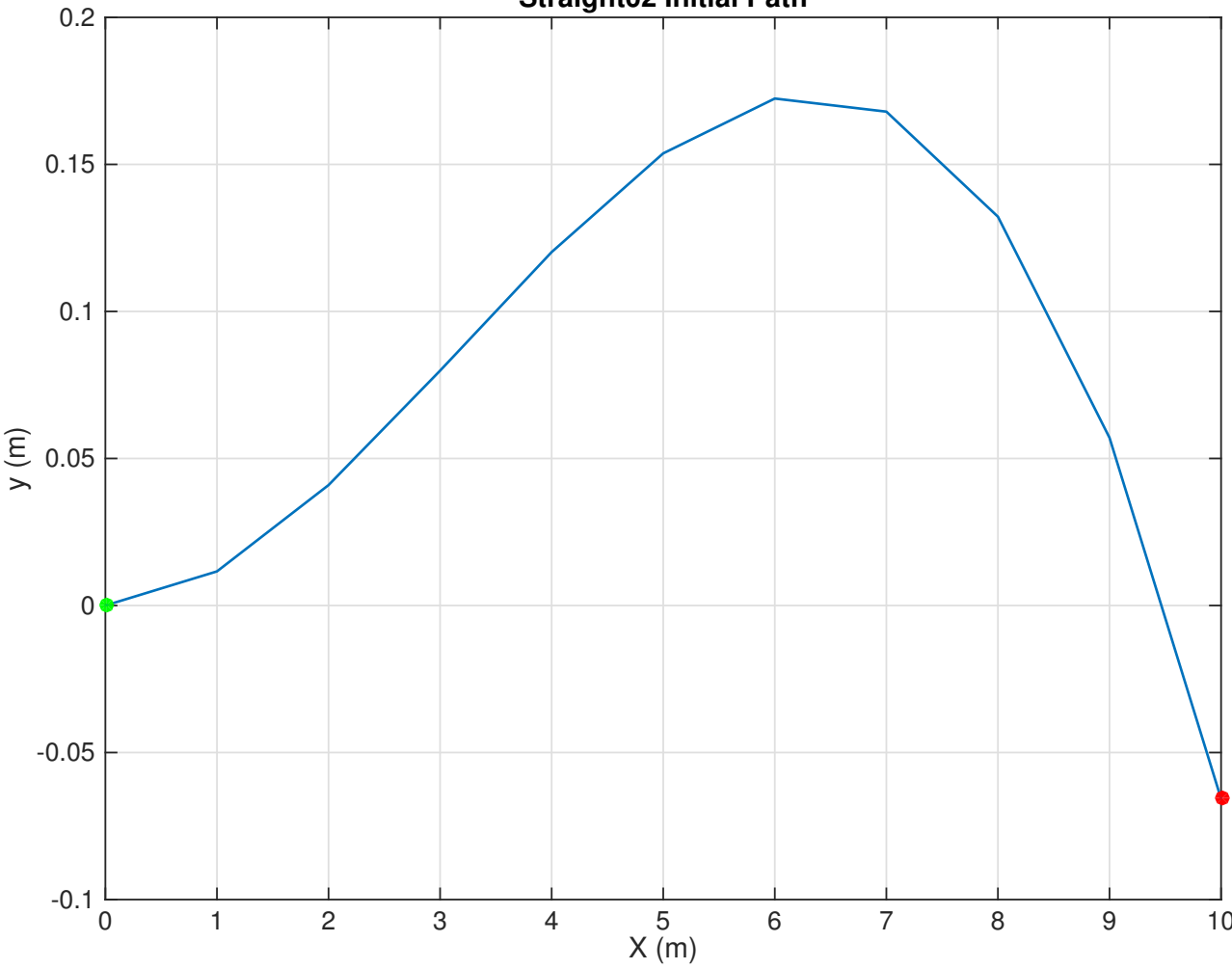
Turns (Clockwise Positive) 1 = 360° turn



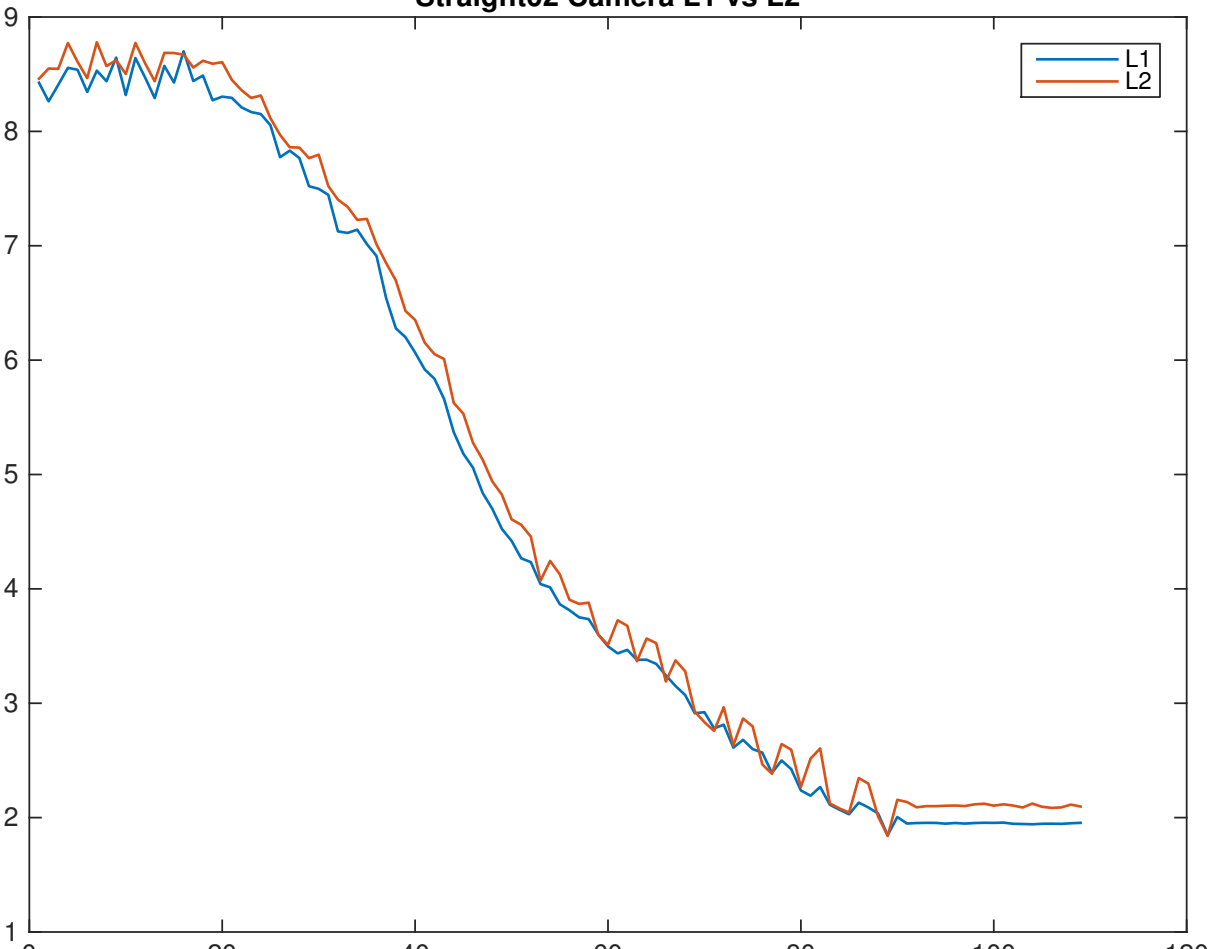
Straight01 Calculated vs. Actual Steering



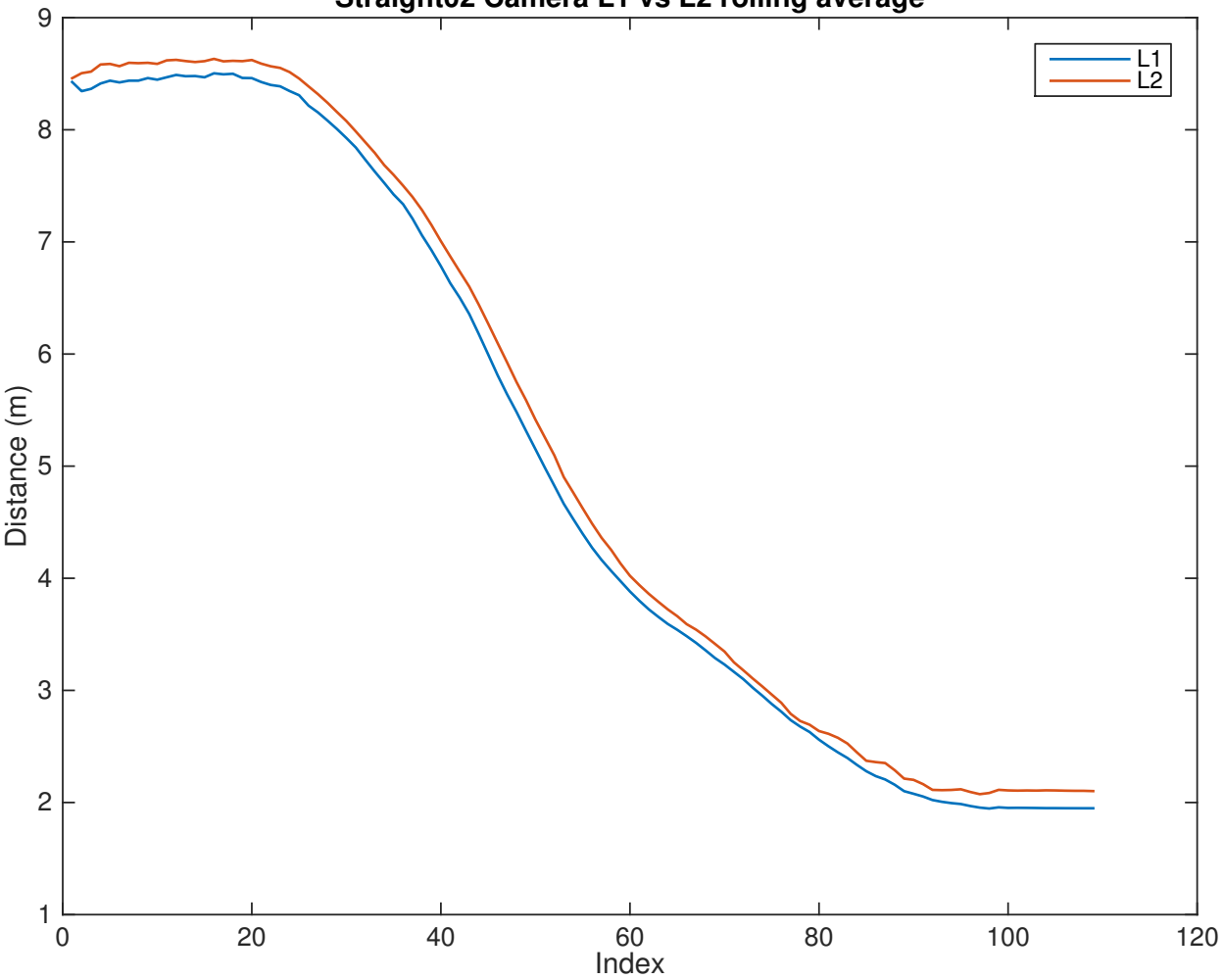
Straight02 Initial Path



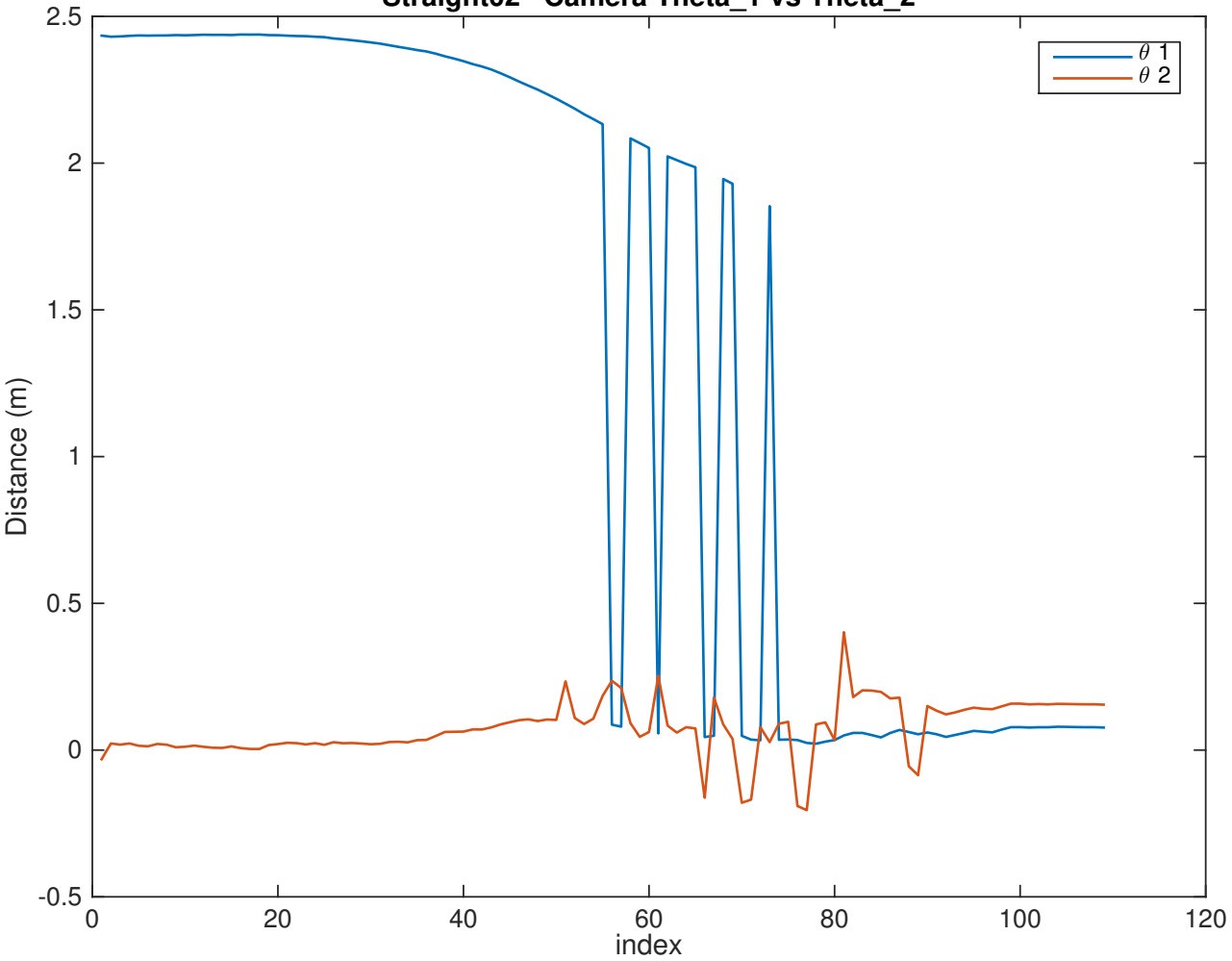
Straight02 Camera L1 vs L2



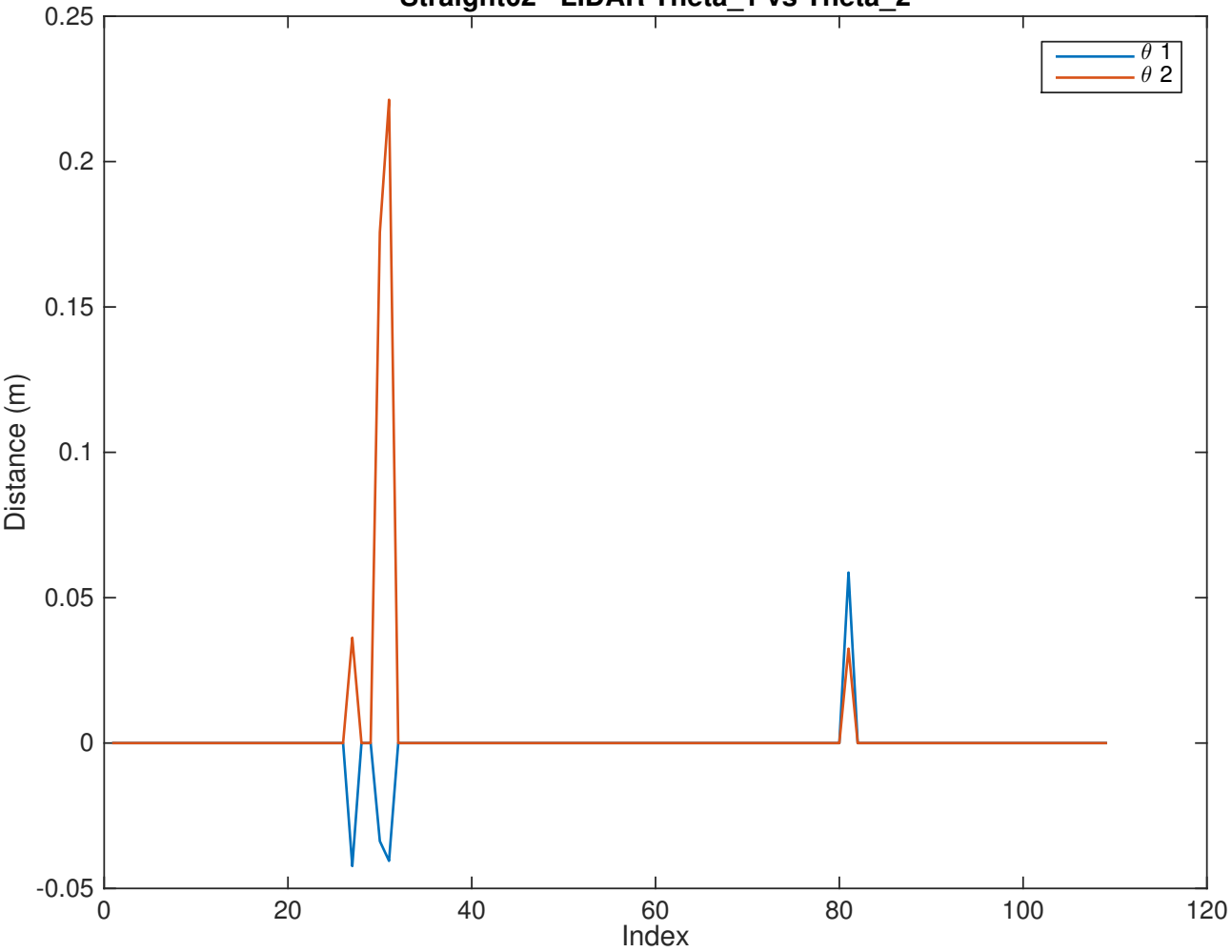
Straight02 Camera L1 vs L2 rolling average



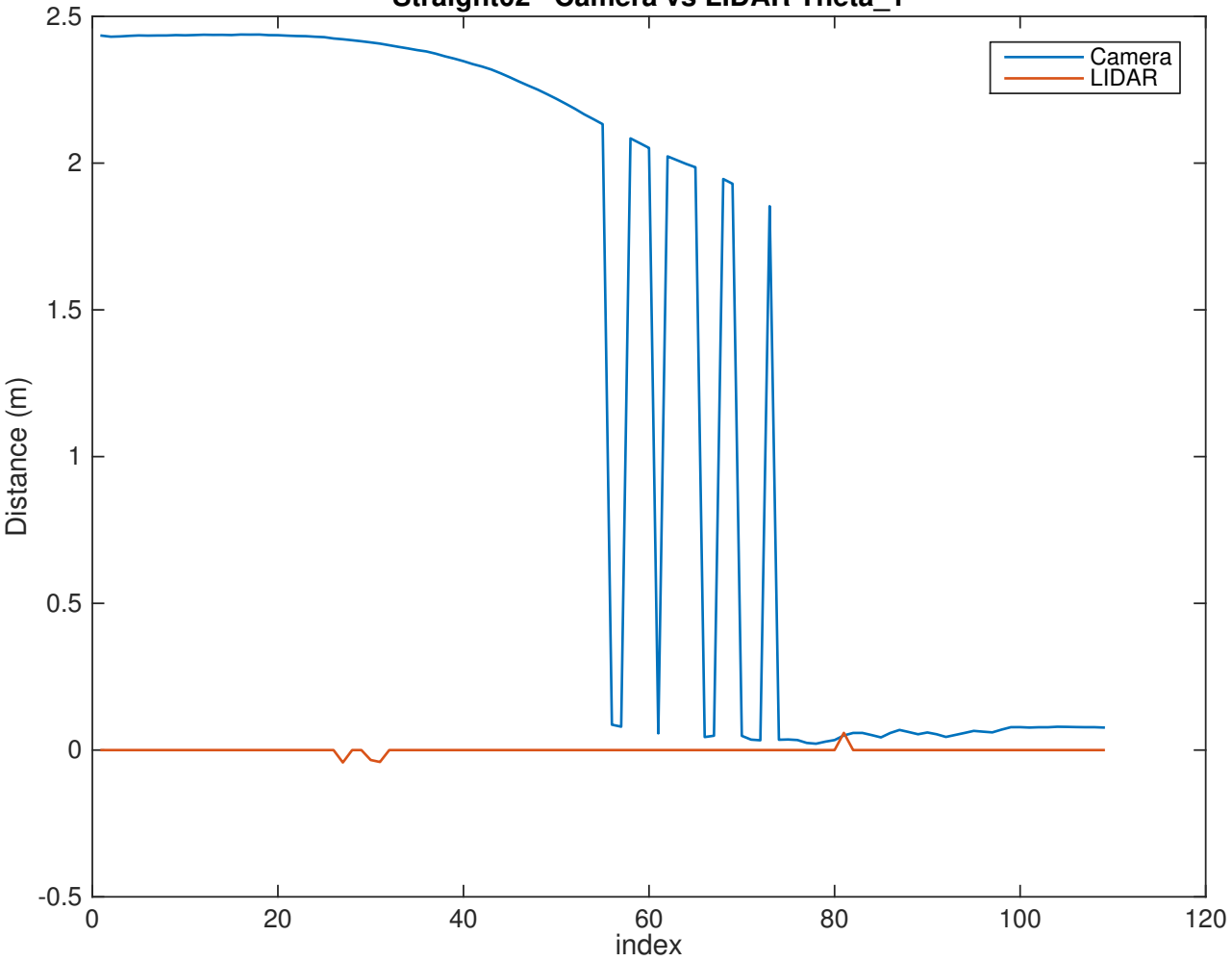
Straight02 Camera Theta_1 vs Theta_2



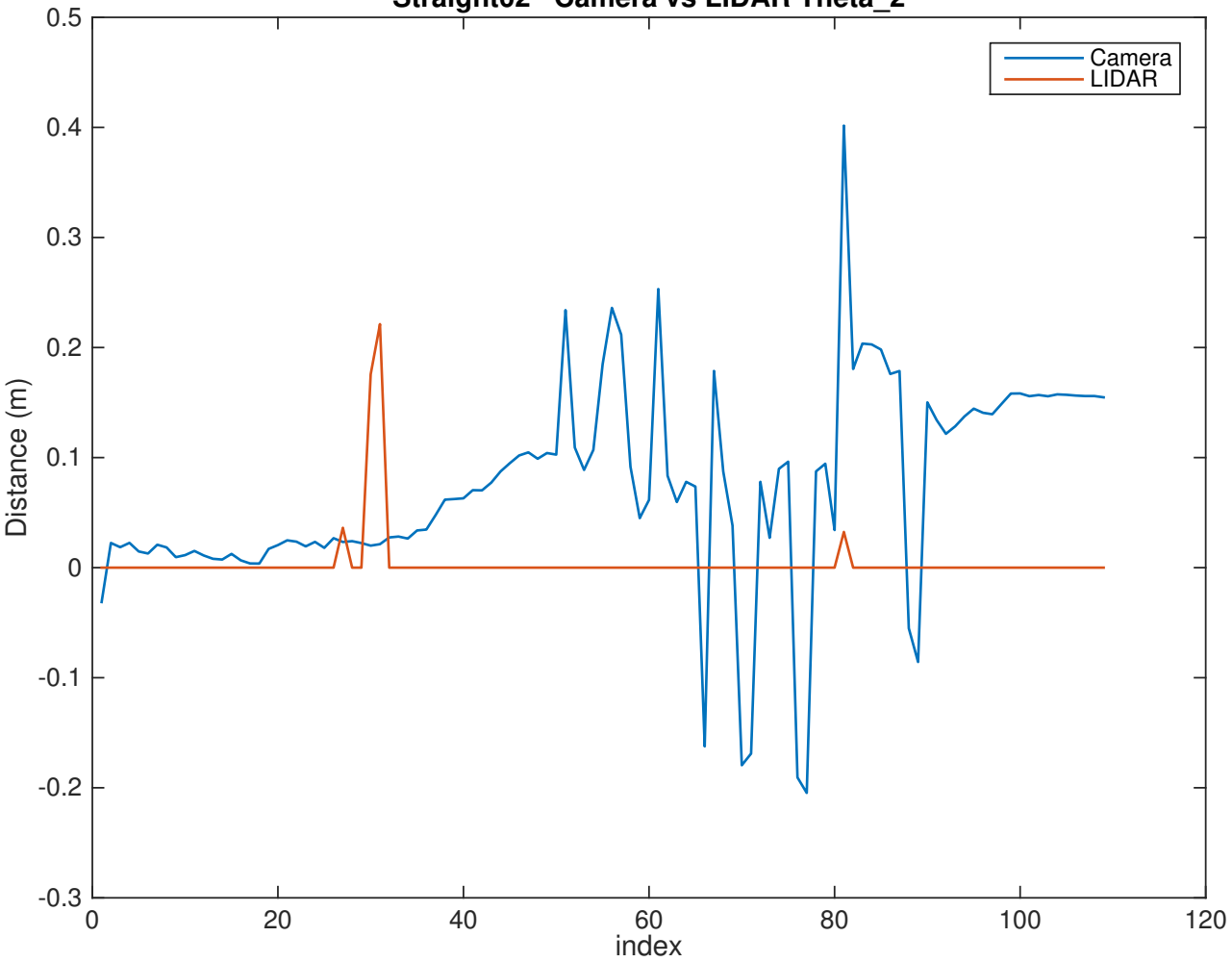
Straight02 LIDAR Theta_1 vs Theta_2



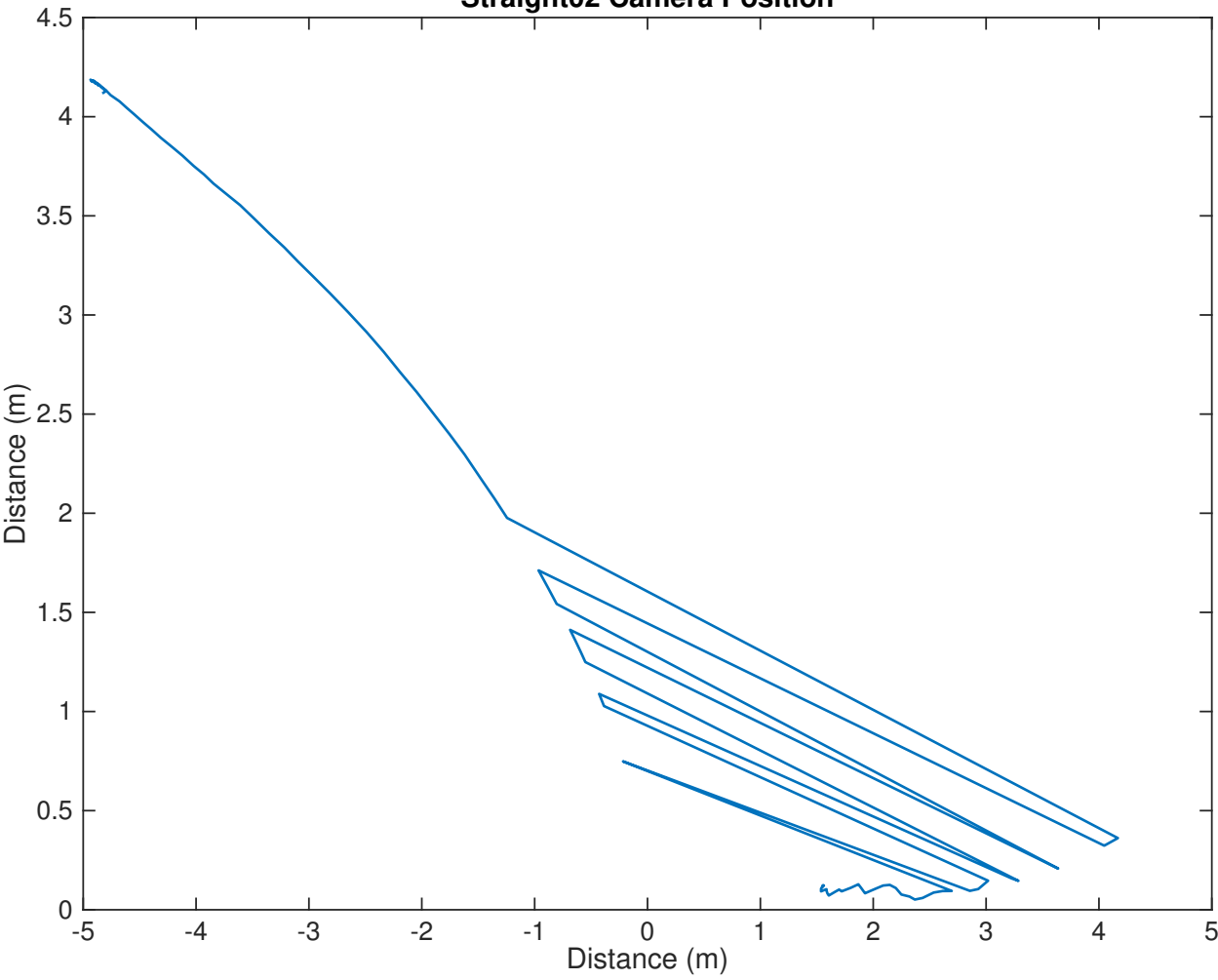
Straight02 Camera vs LIDAR Theta_1



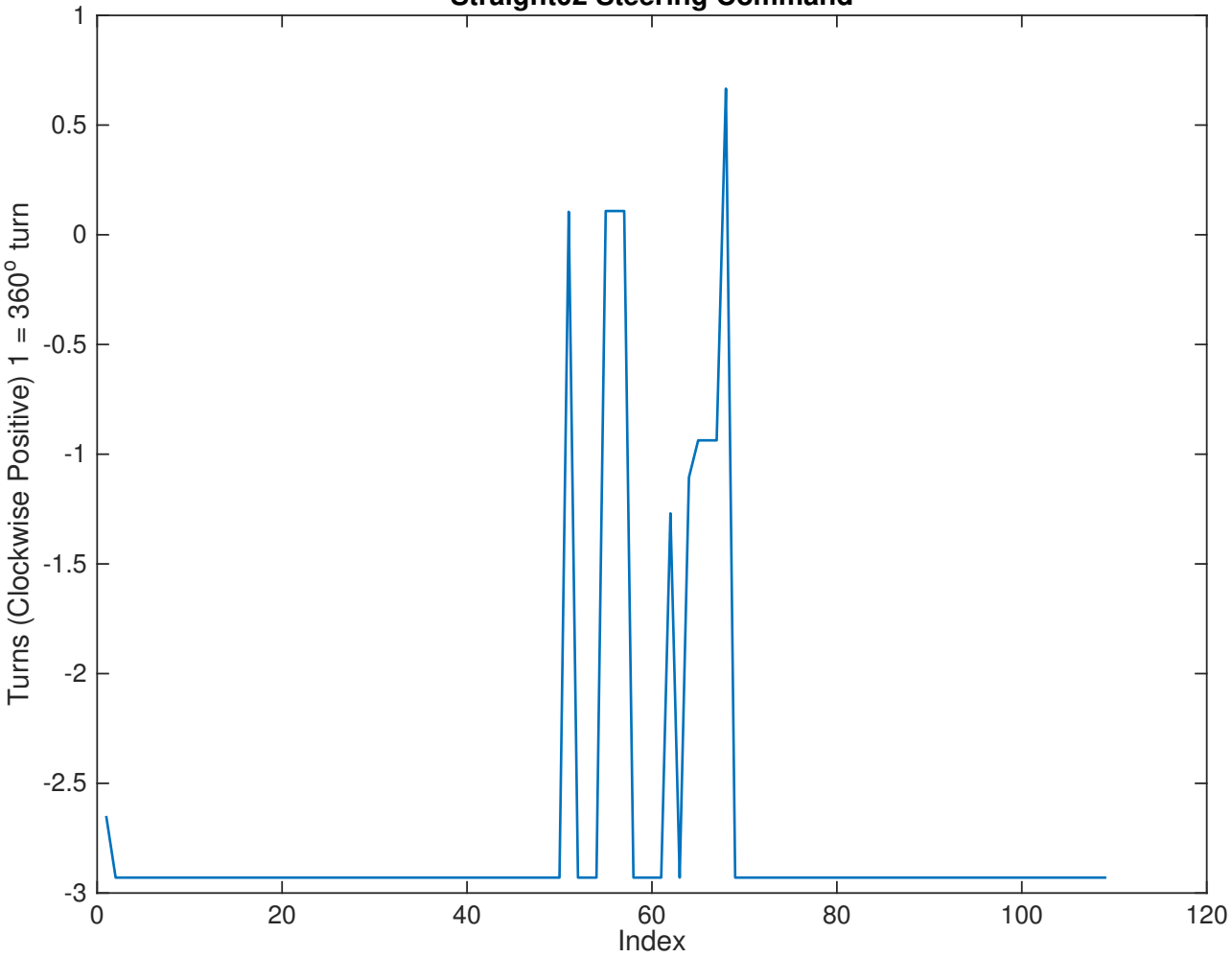
Straight02 Camera vs LIDAR Theta_2



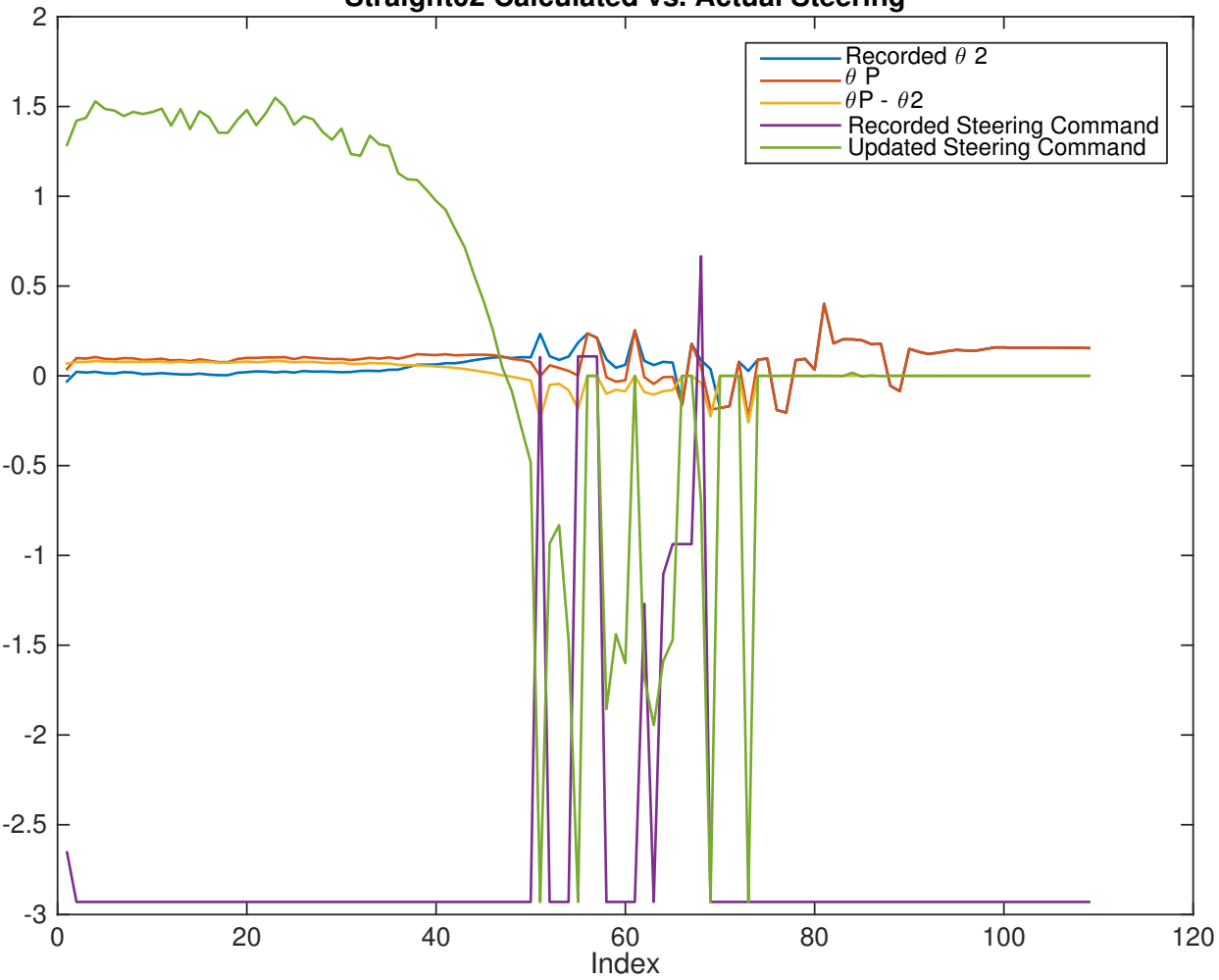
Straight02 Camera Position



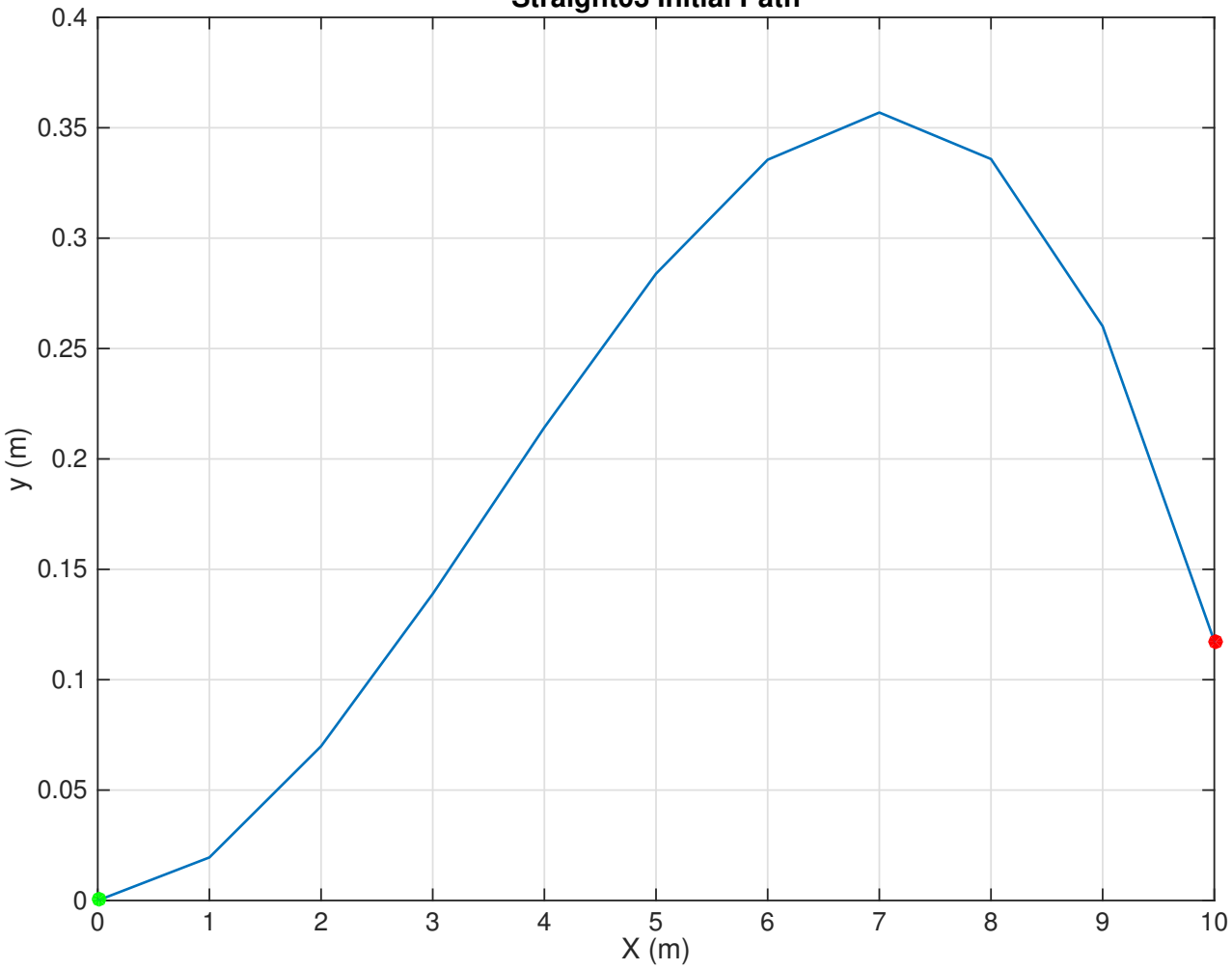
Straight02 Steering Command



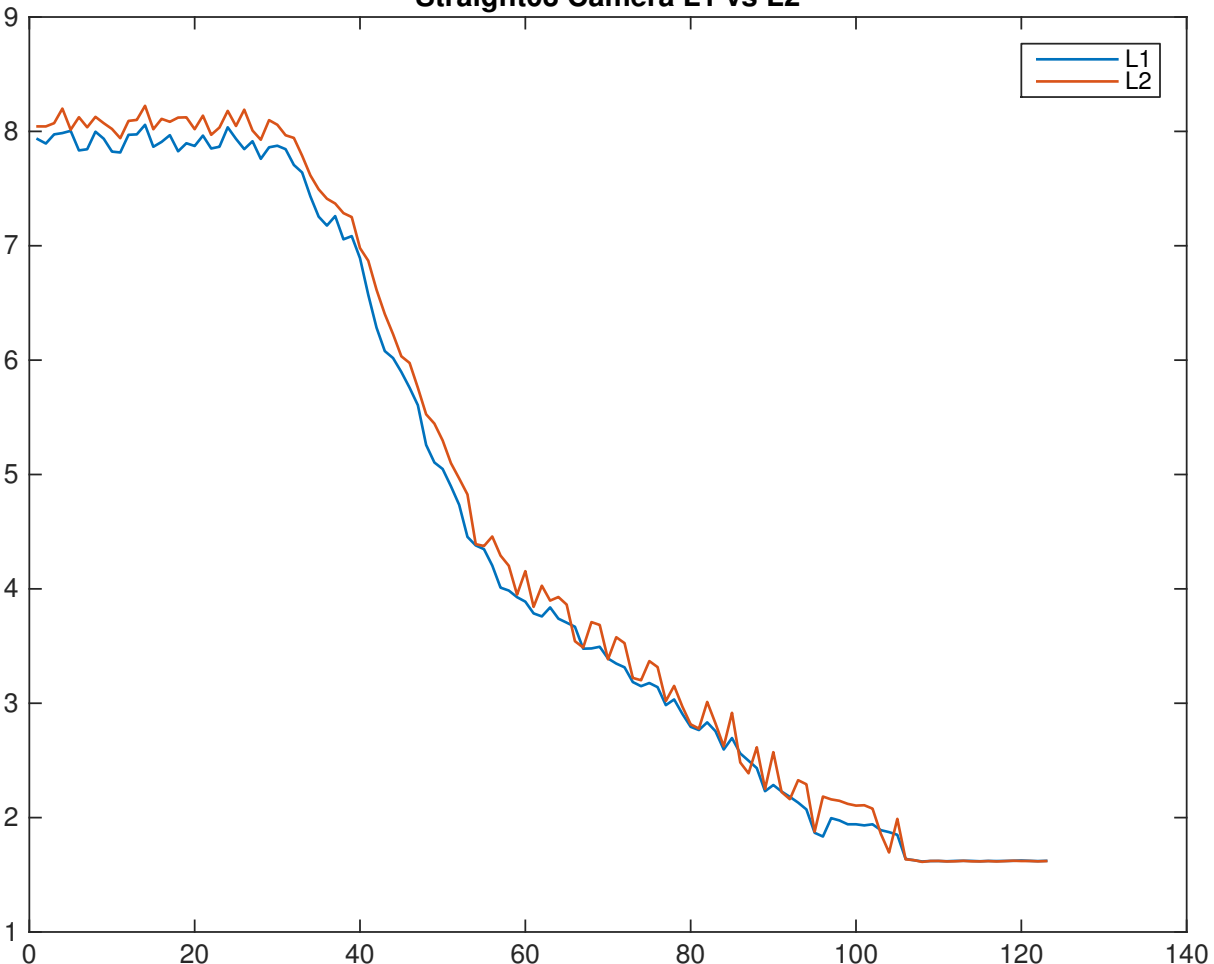
Straight02 Calculated vs. Actual Steering



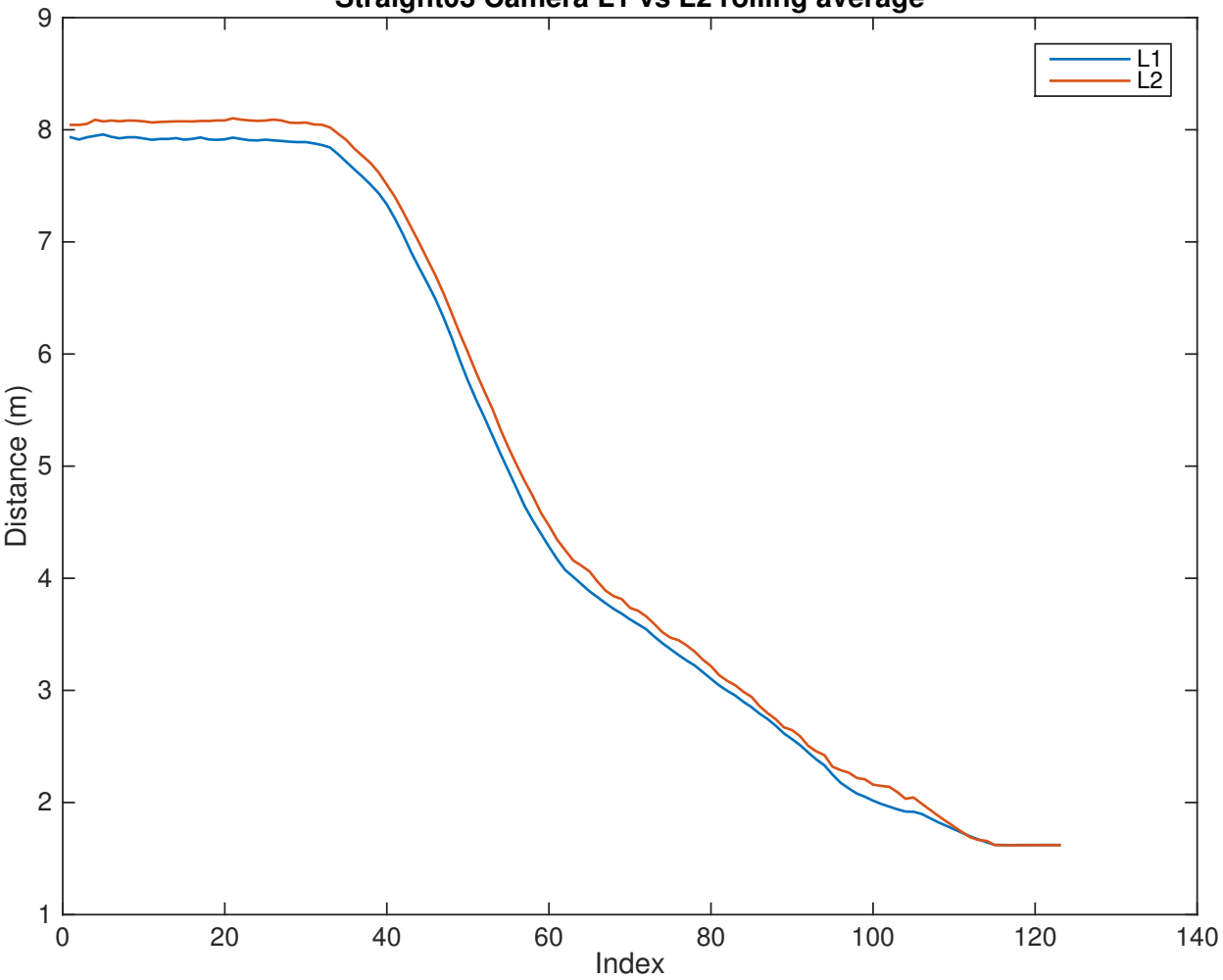
Straight03 Initial Path



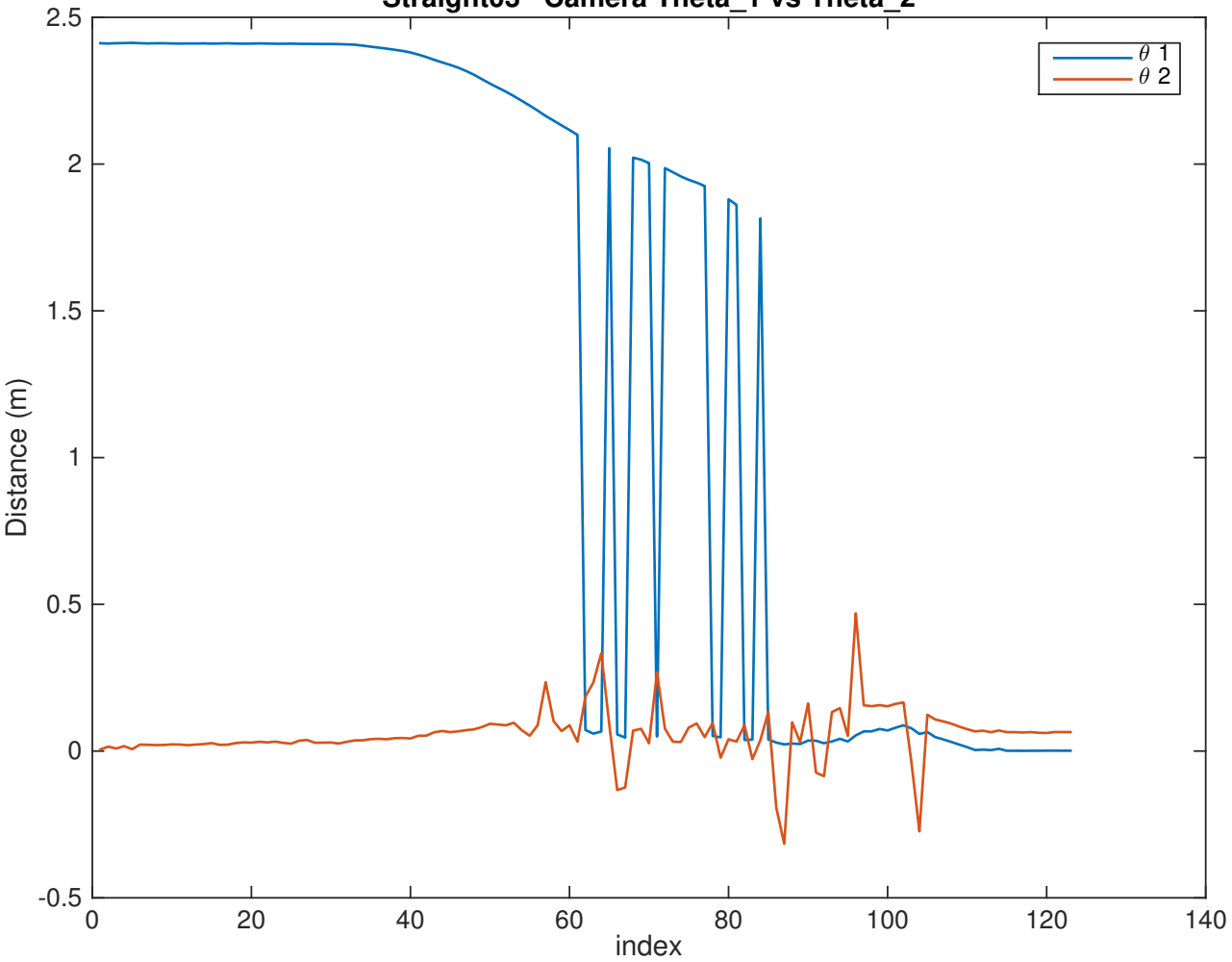
Straight03 Camera L1 vs L2



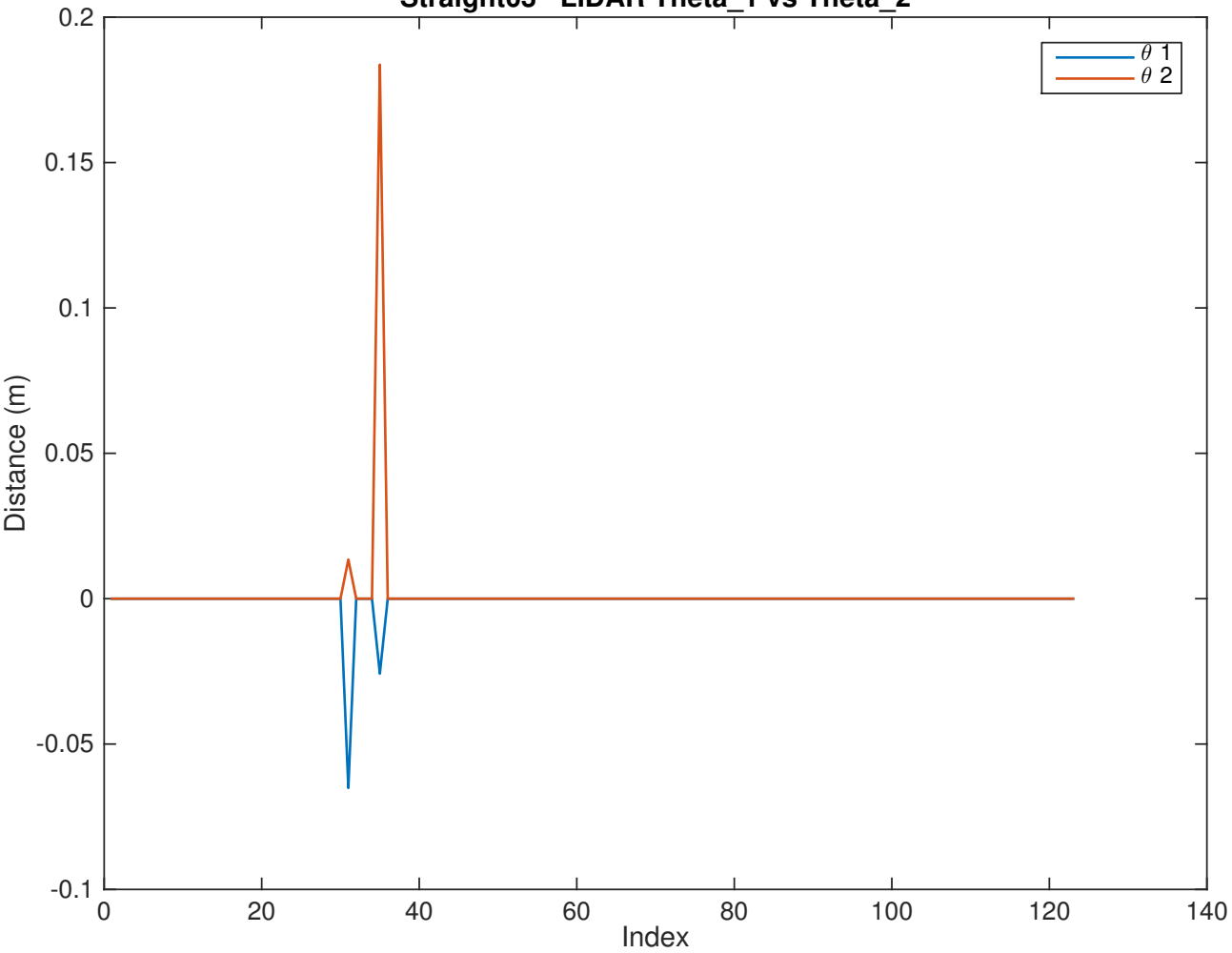
Straight03 Camera L1 vs L2 rolling average



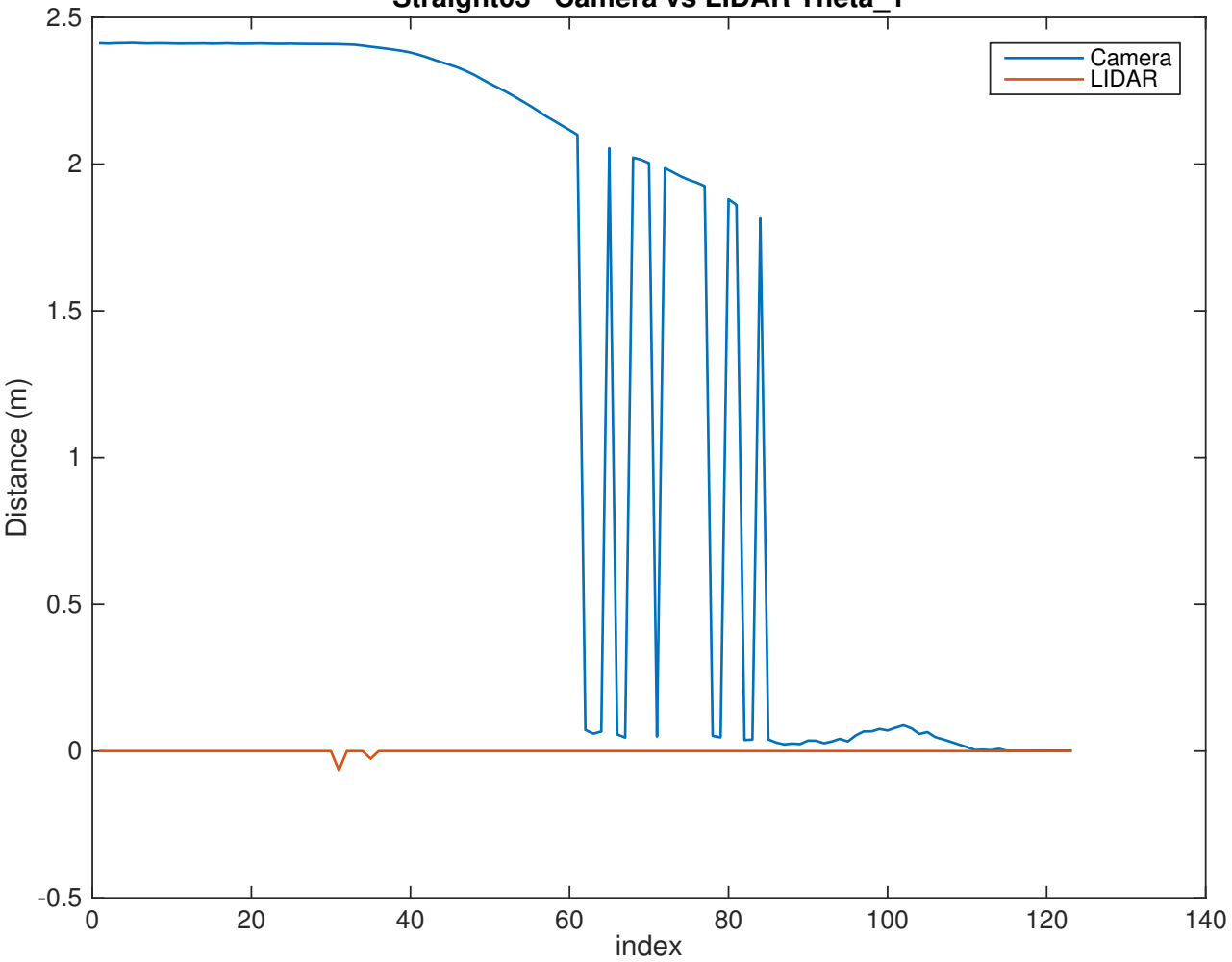
Straight03 Camera Theta_1 vs Theta_2



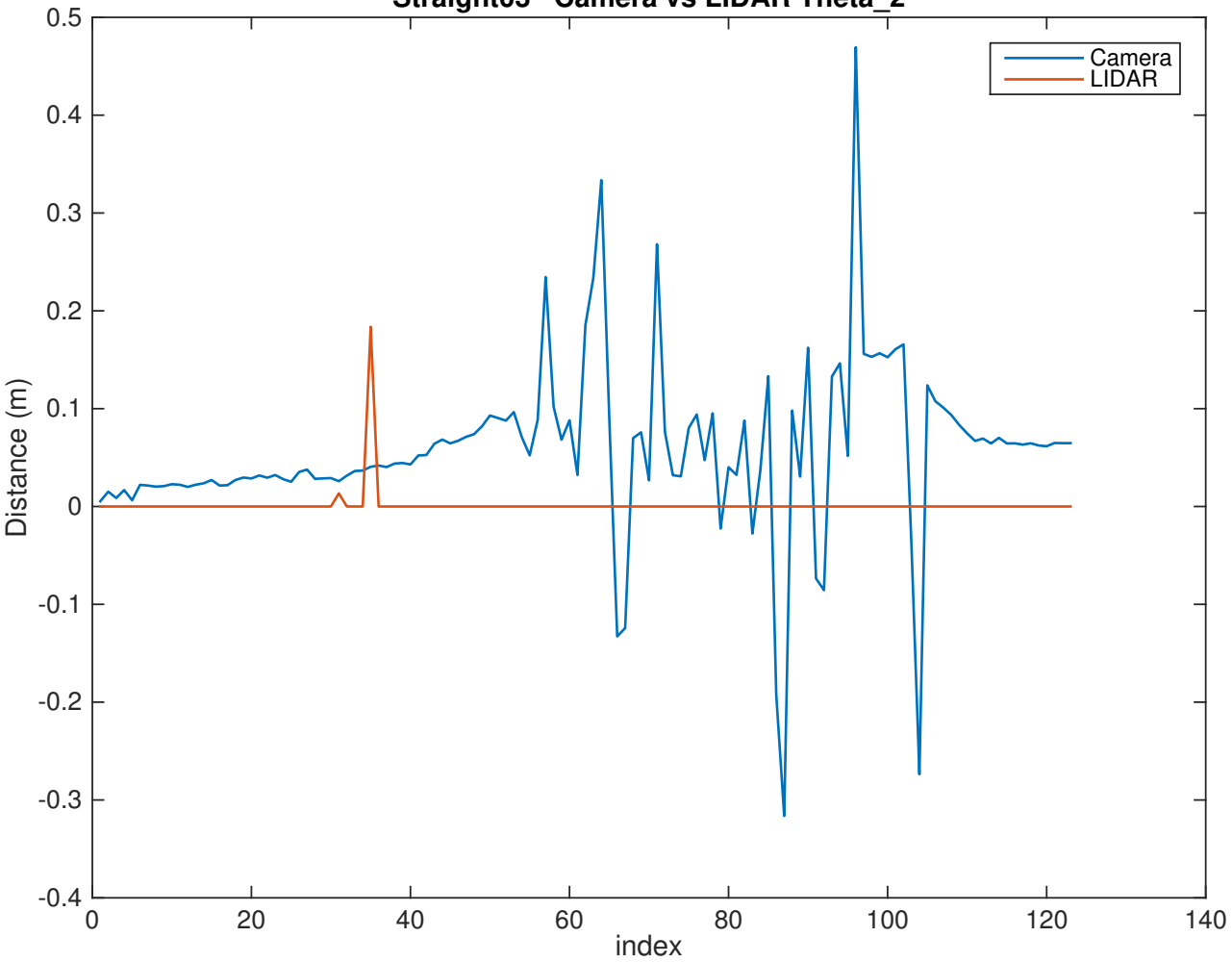
Straight03 LIDAR Theta_1 vs Theta_2



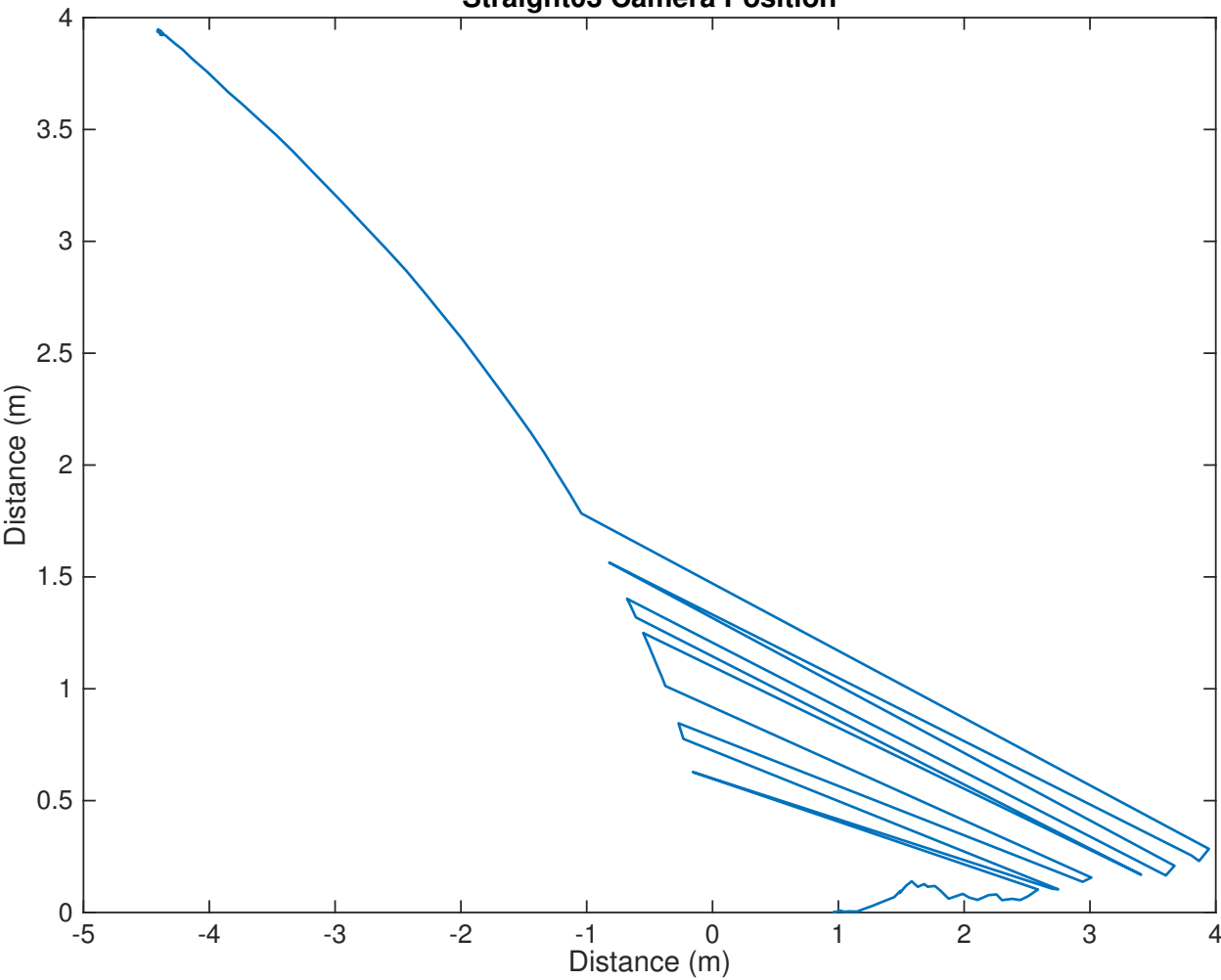
Straight03 Camera vs LIDAR Theta_1



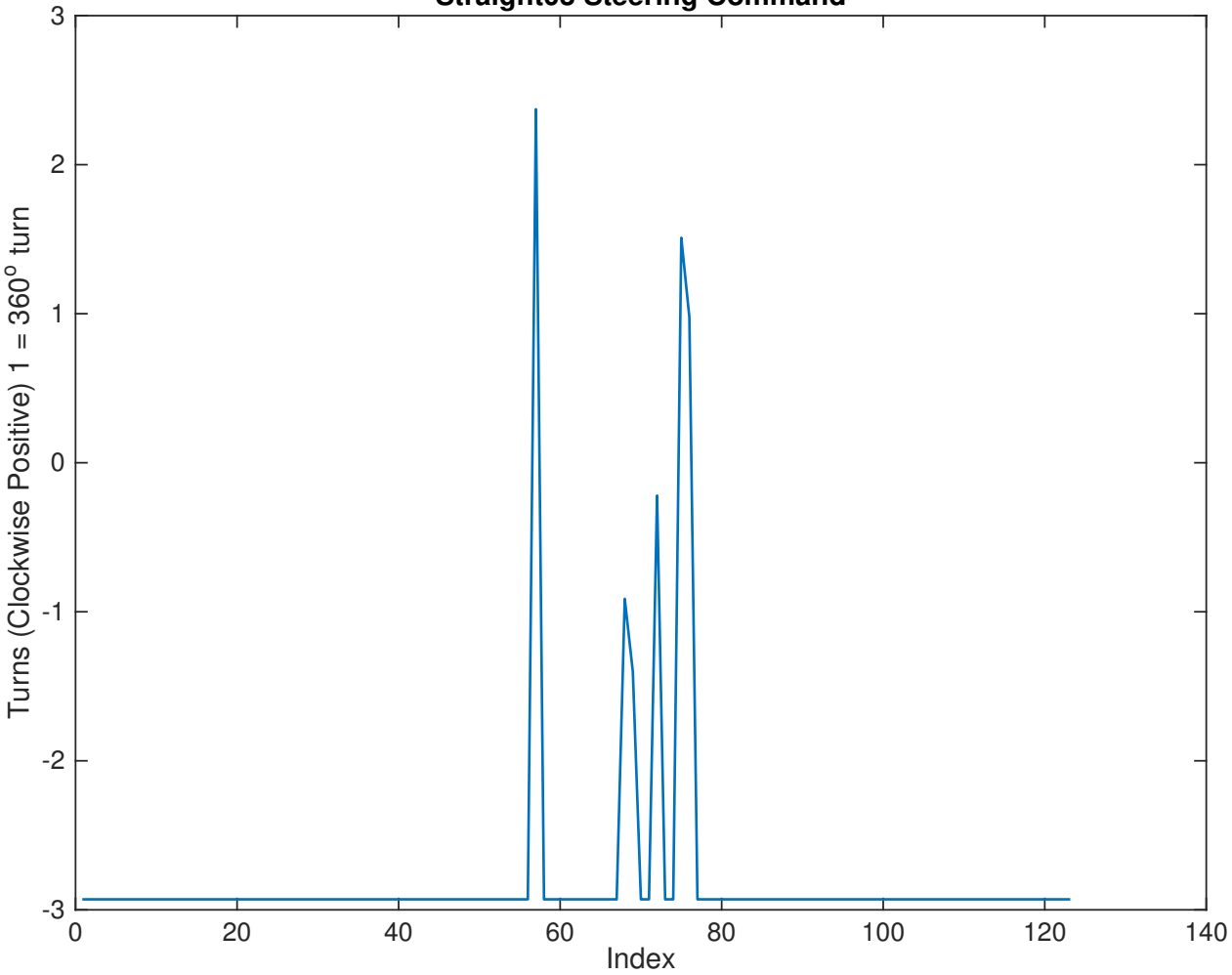
Straight03 Camera vs LIDAR Theta_2



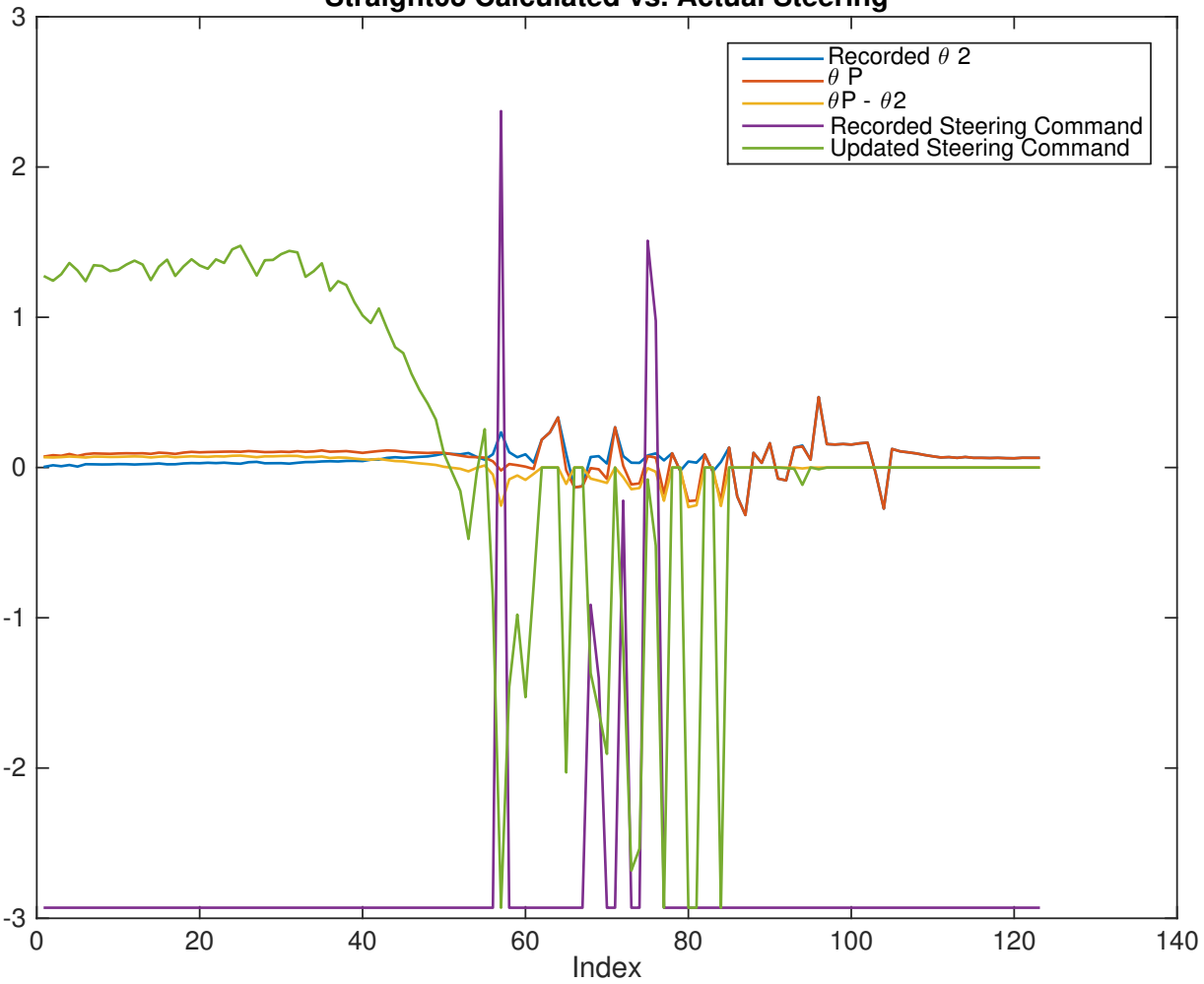
Straight03 Camera Position



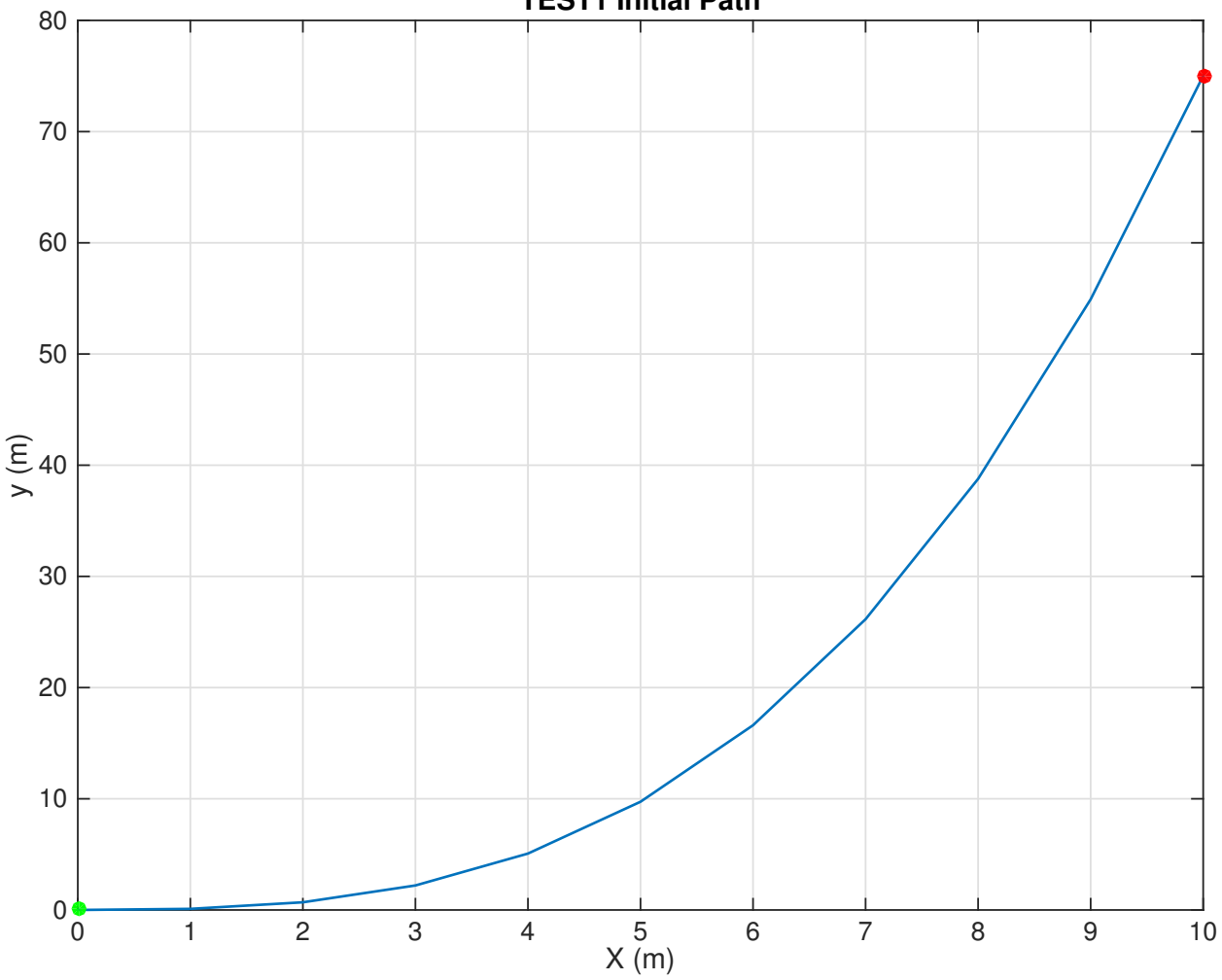
Straight03 Steering Command



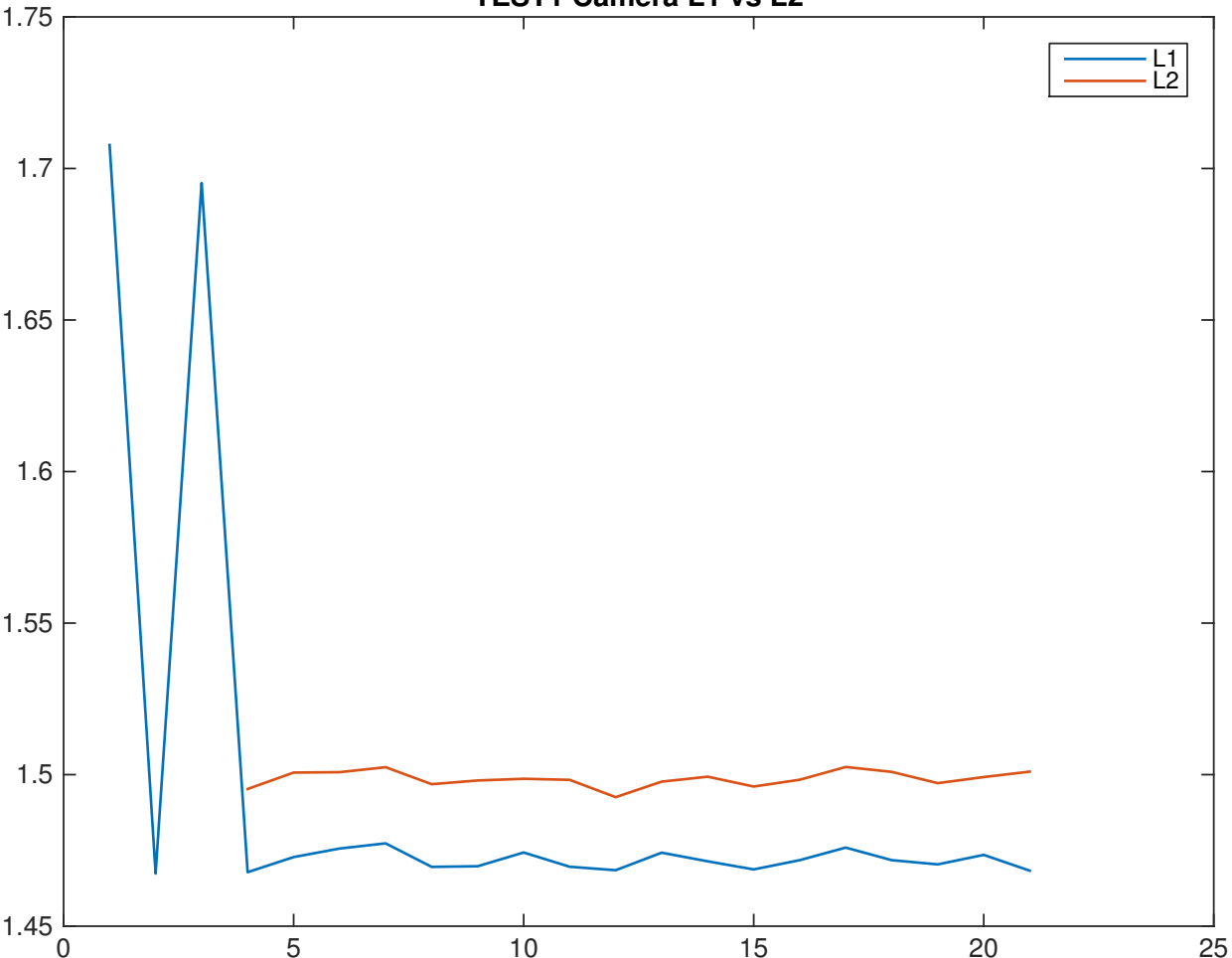
Straight03 Calculated vs. Actual Steering



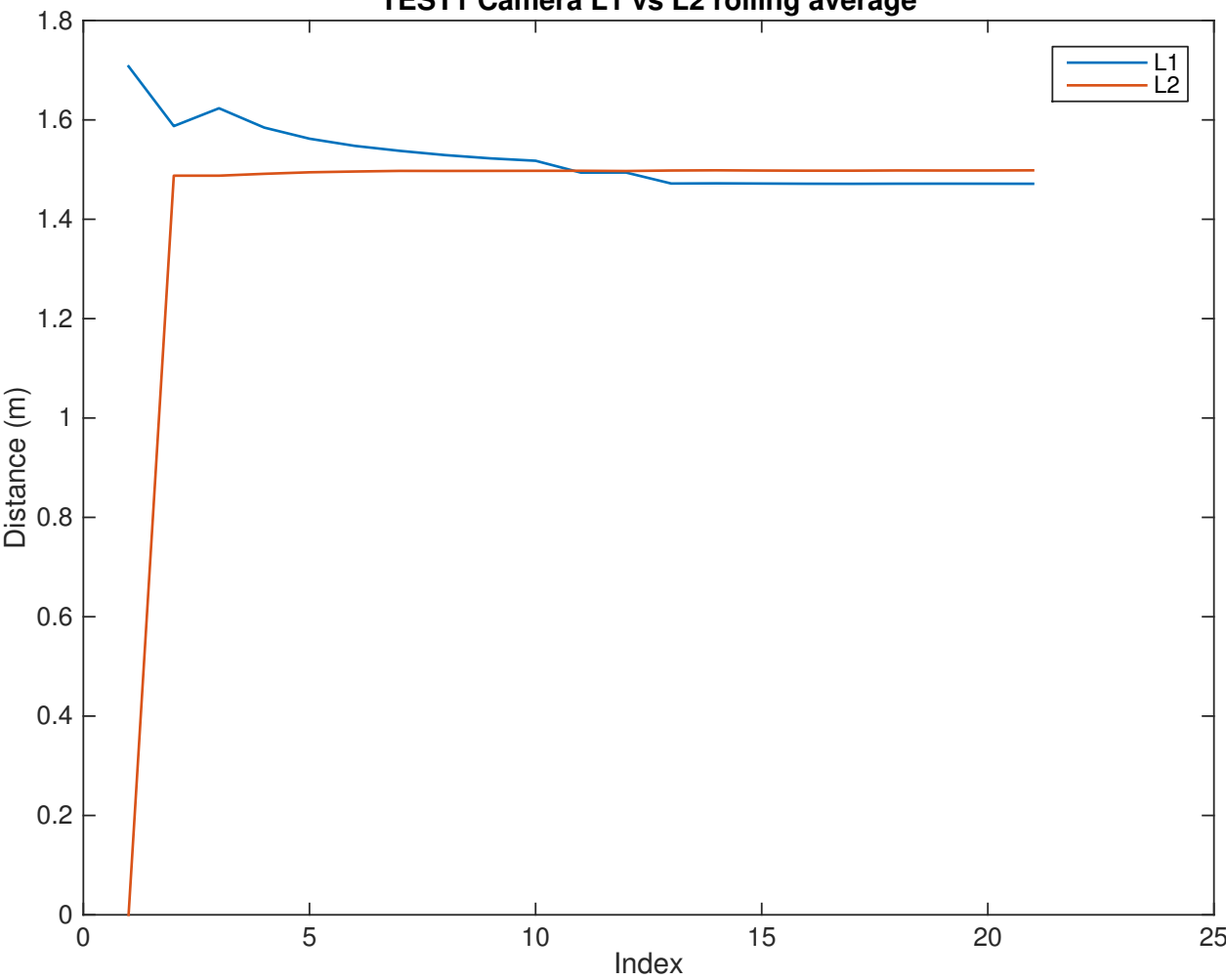
TEST1 Initial Path



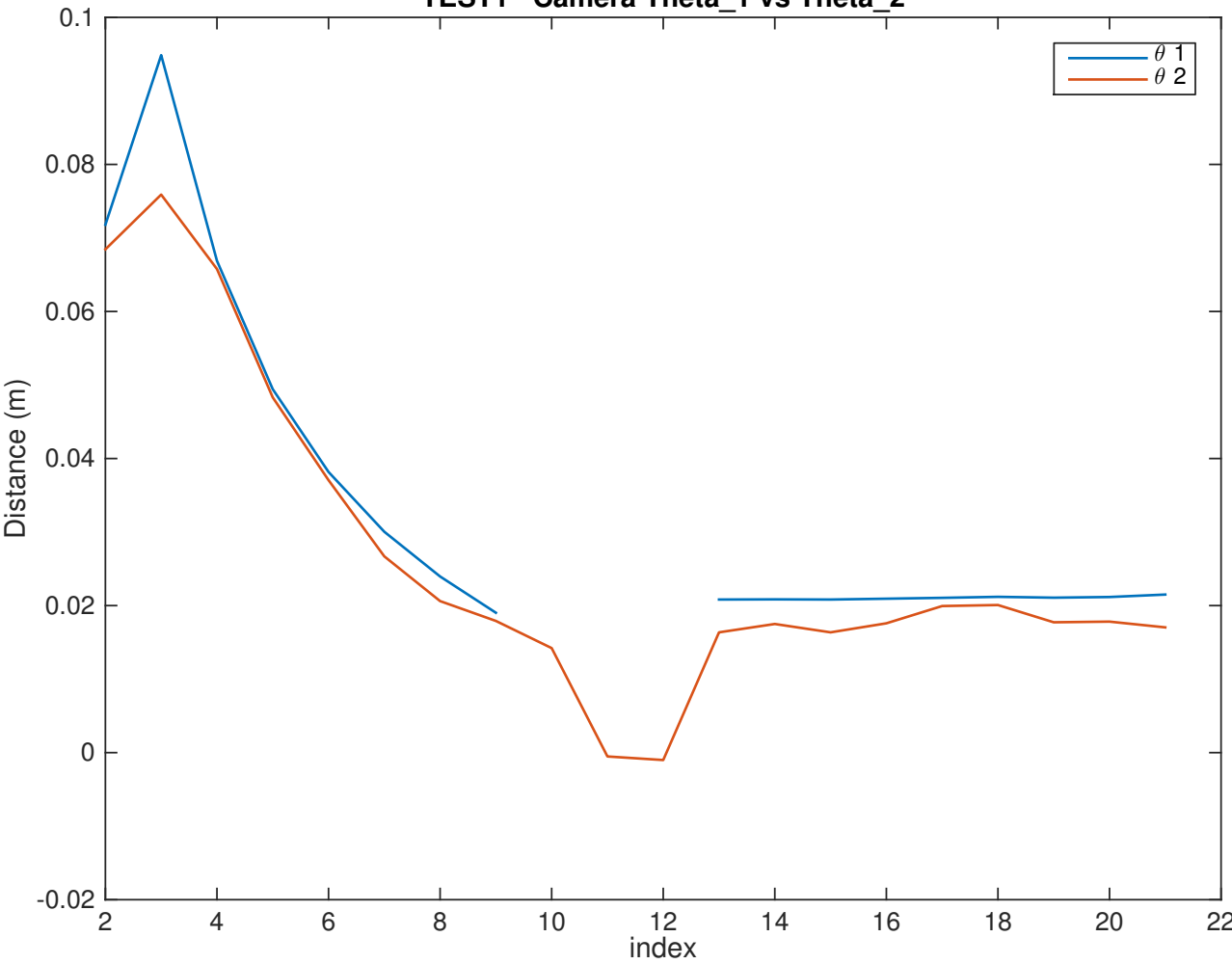
TEST1 Camera L1 vs L2



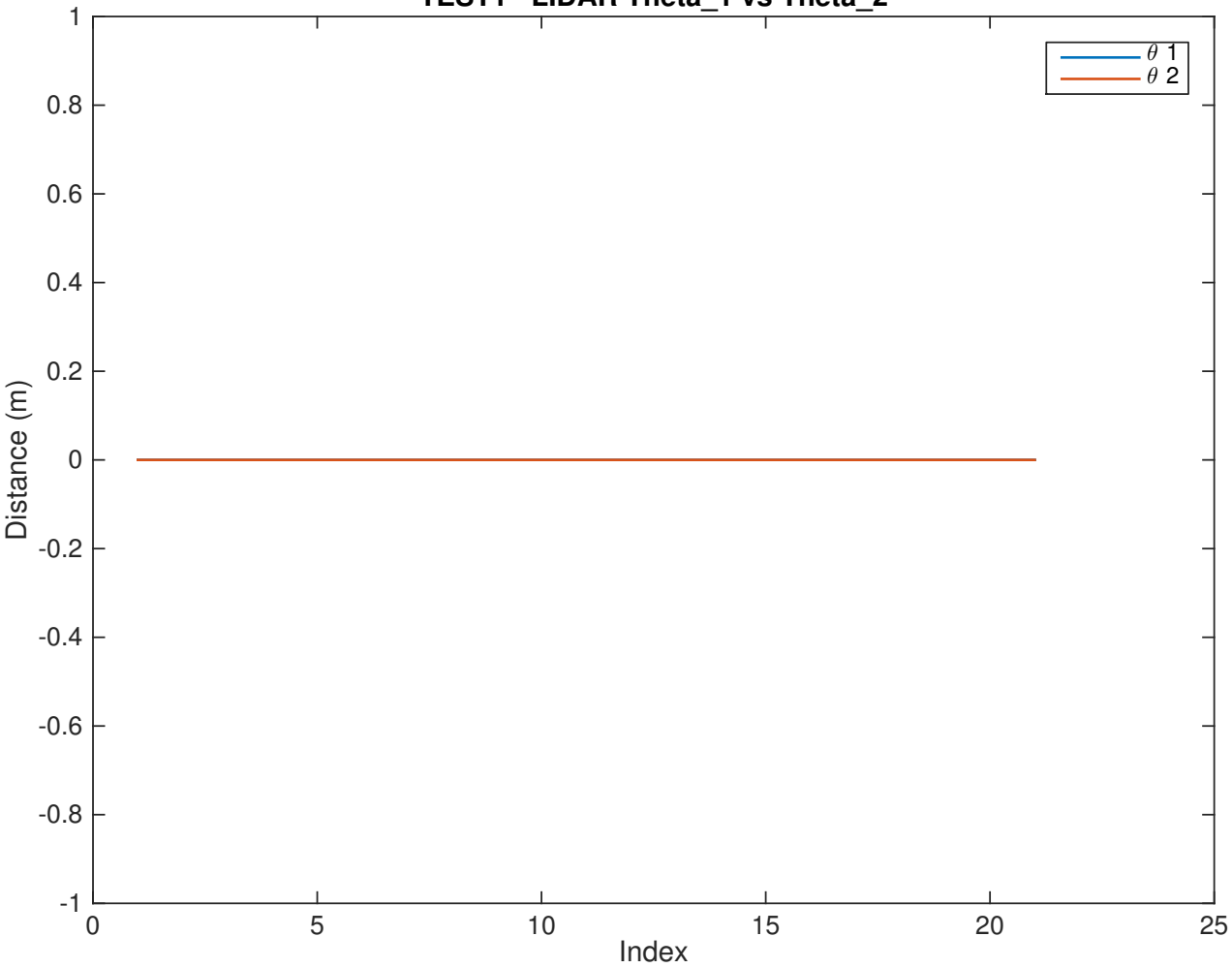
TEST1 Camera L1 vs L2 rolling average



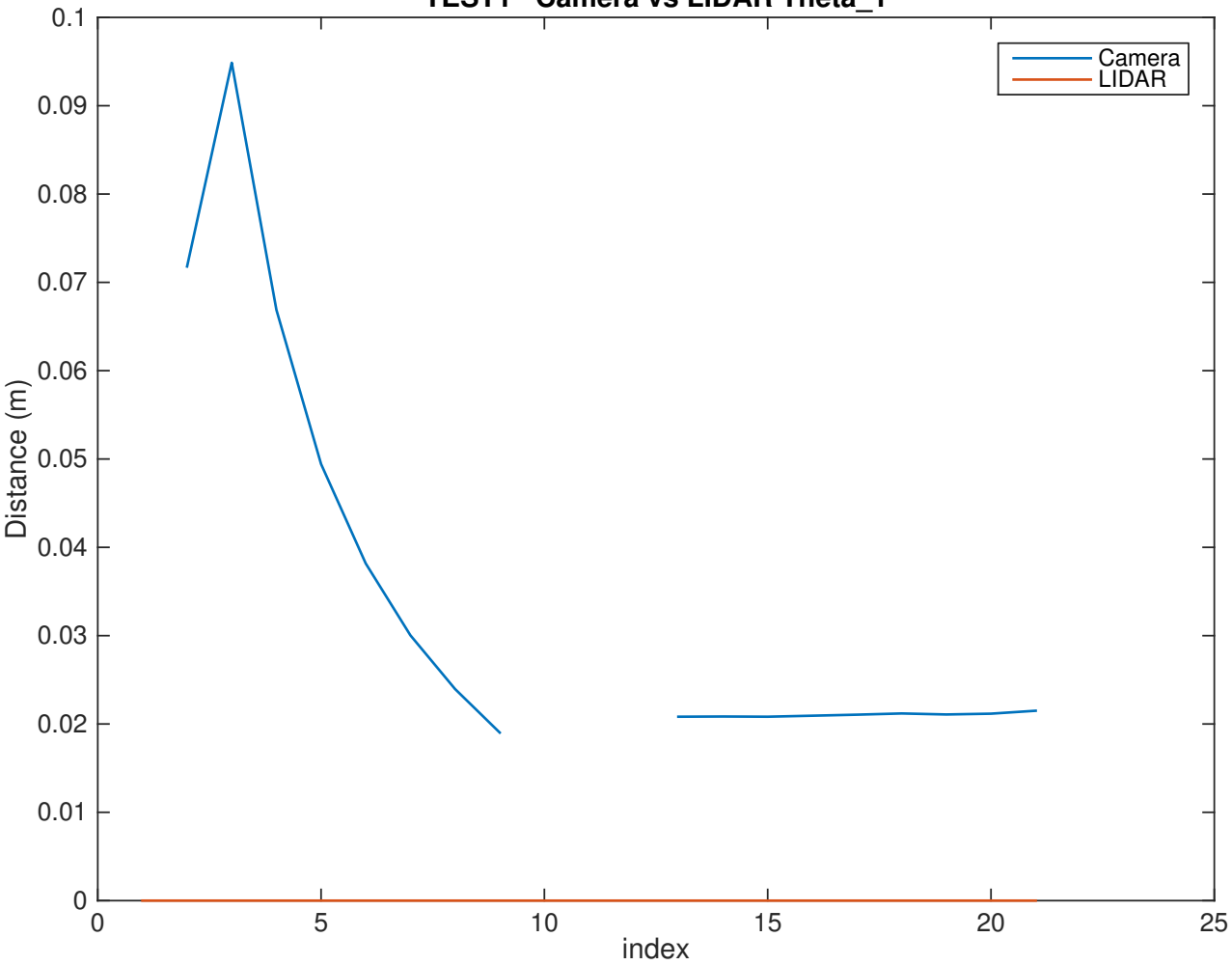
TEST1 Camera Theta_1 vs Theta_2



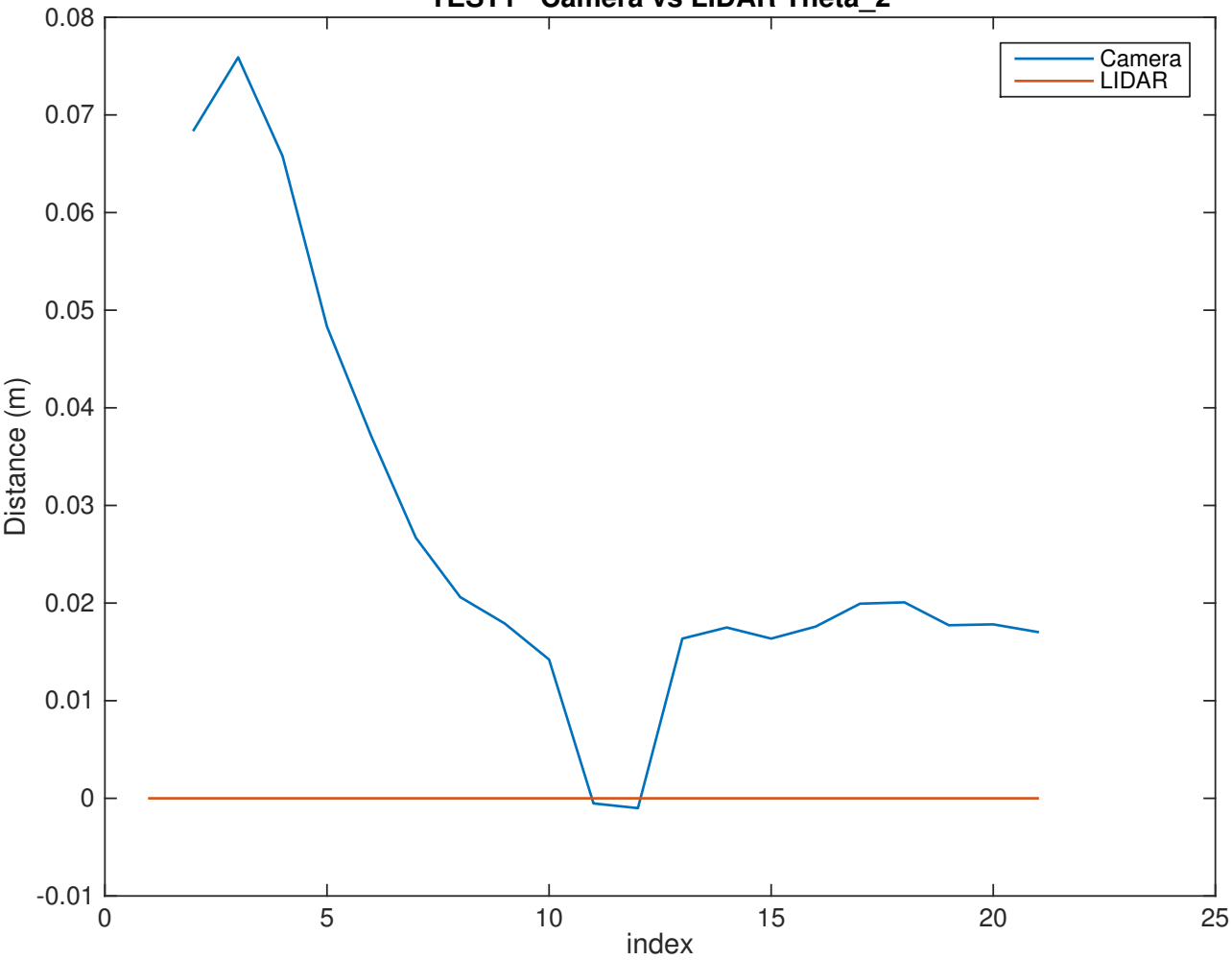
TEST1 LIDAR Theta_1 vs Theta_2



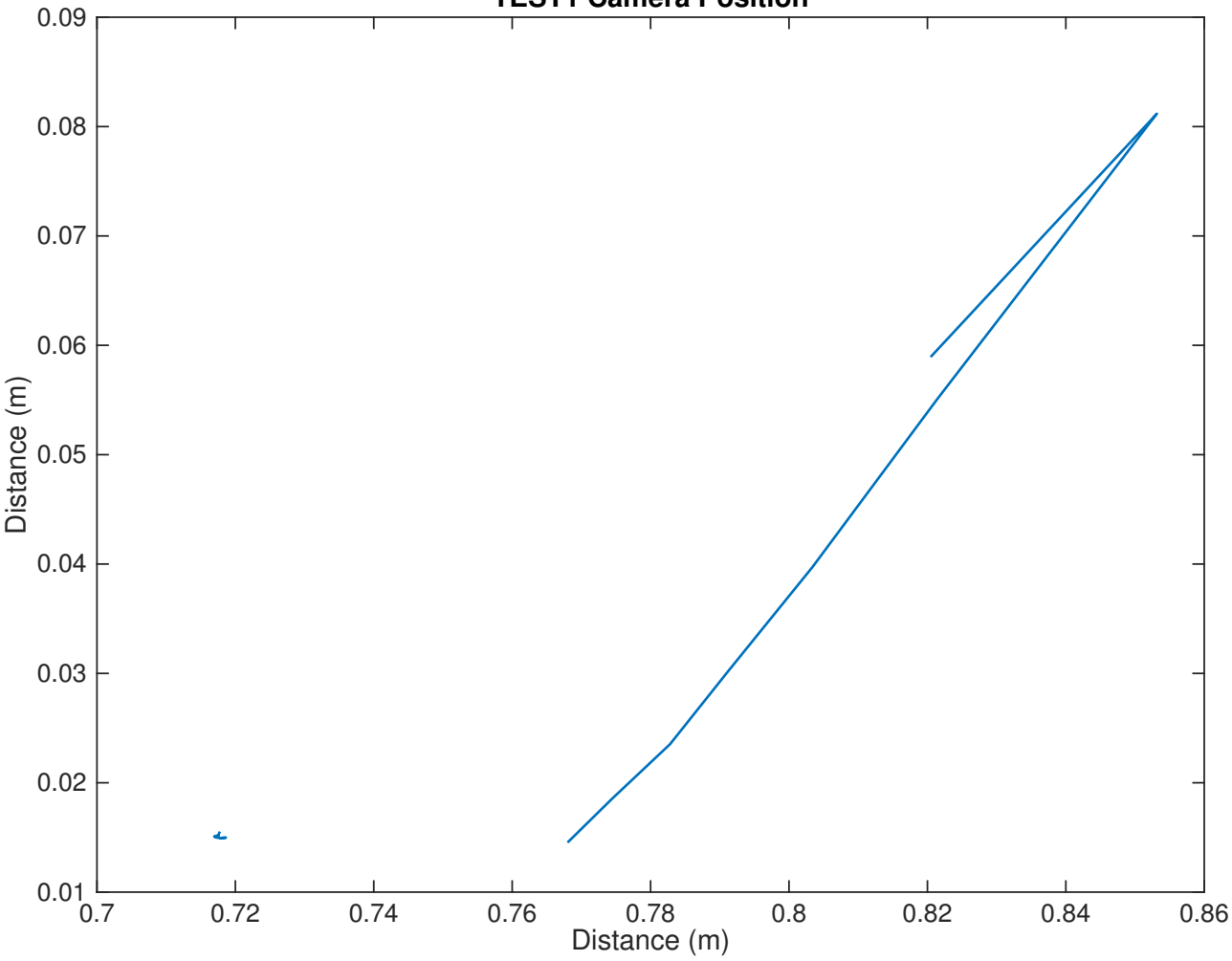
TEST1 Camera vs LIDAR Theta_1



TEST1 Camera vs LIDAR Theta_2



TEST1 Camera Position



TEST1 Steering Command

