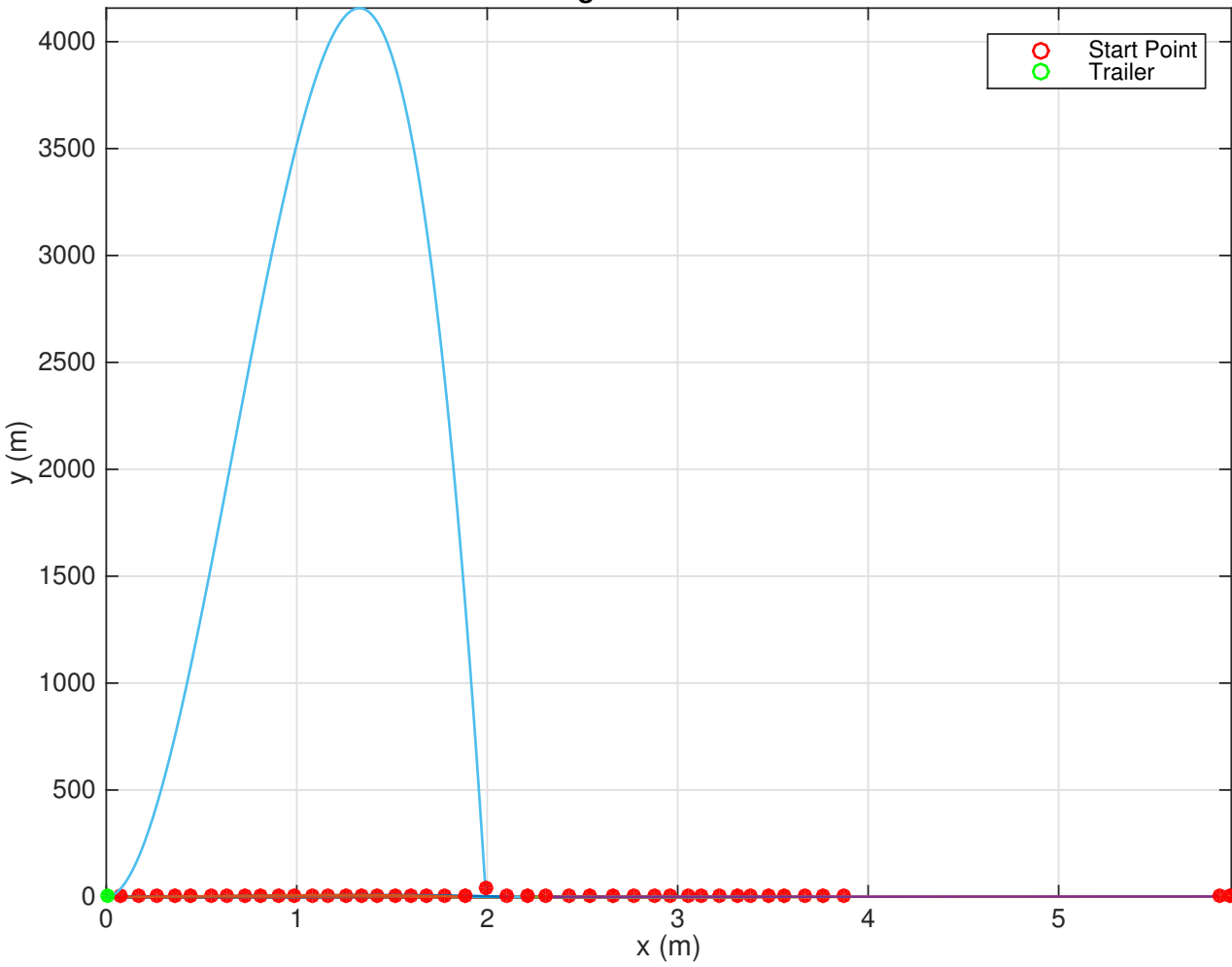


Angled01 All Paths



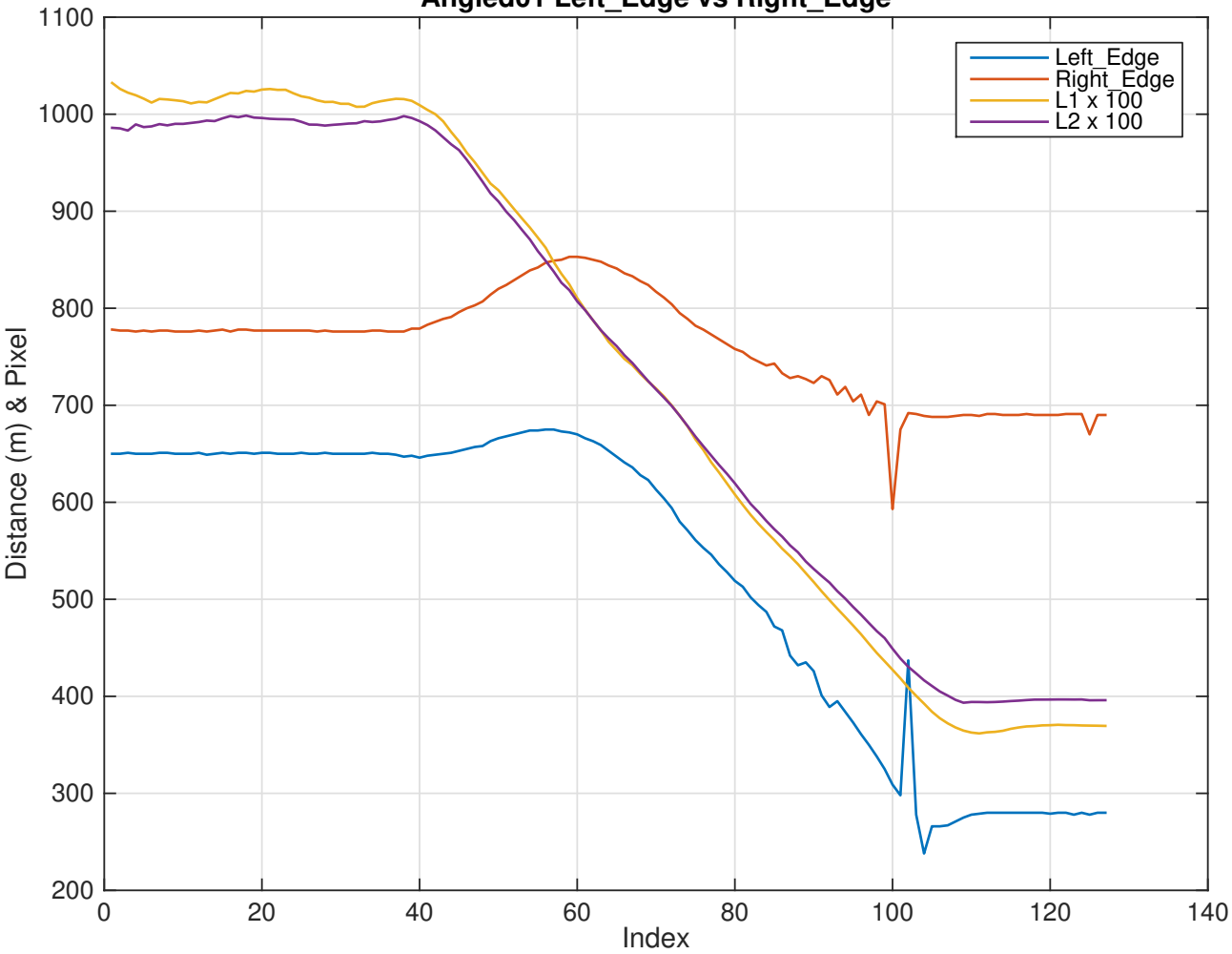
Number_Of_Unique_Paths

King_Pin_Detected

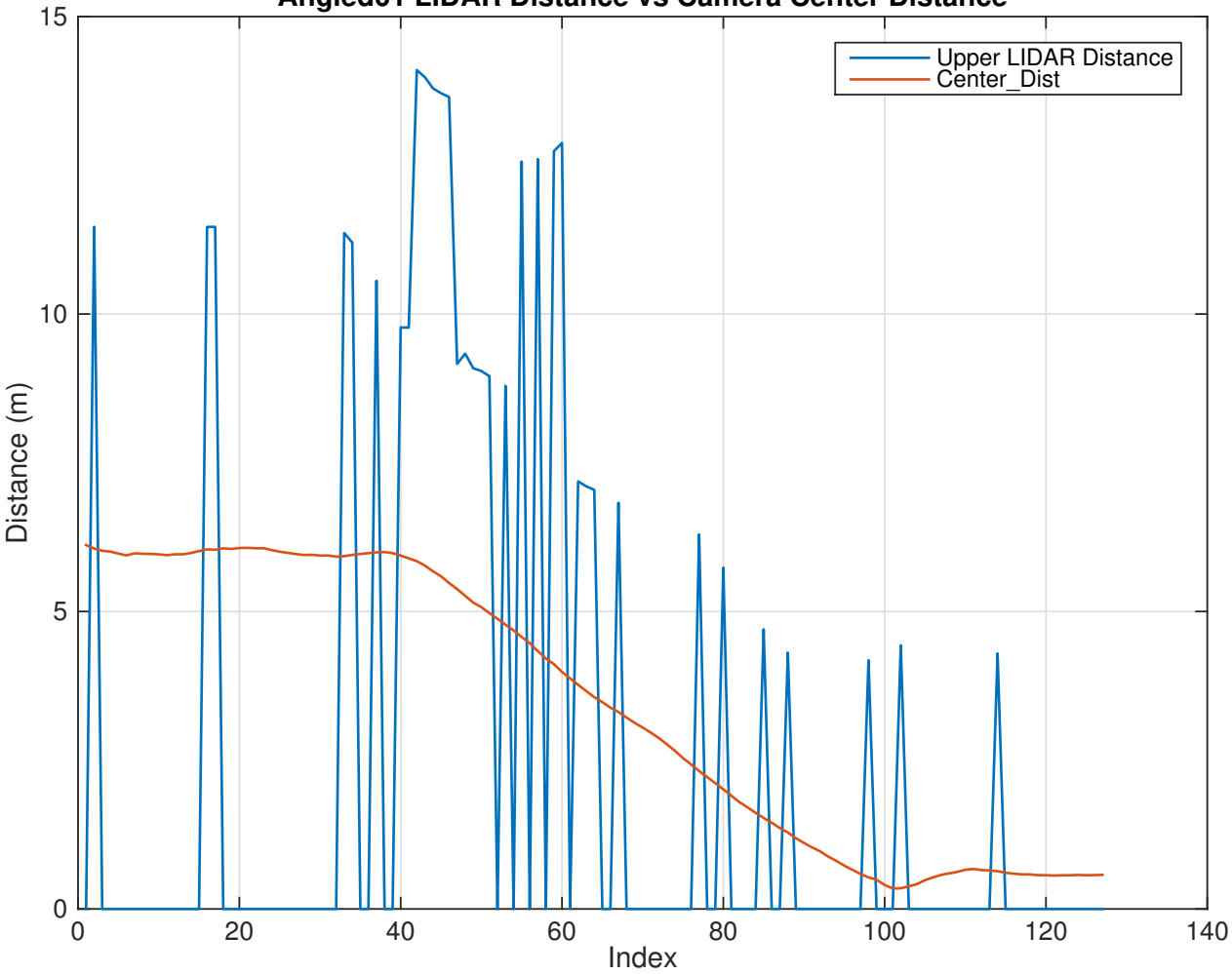
22

false

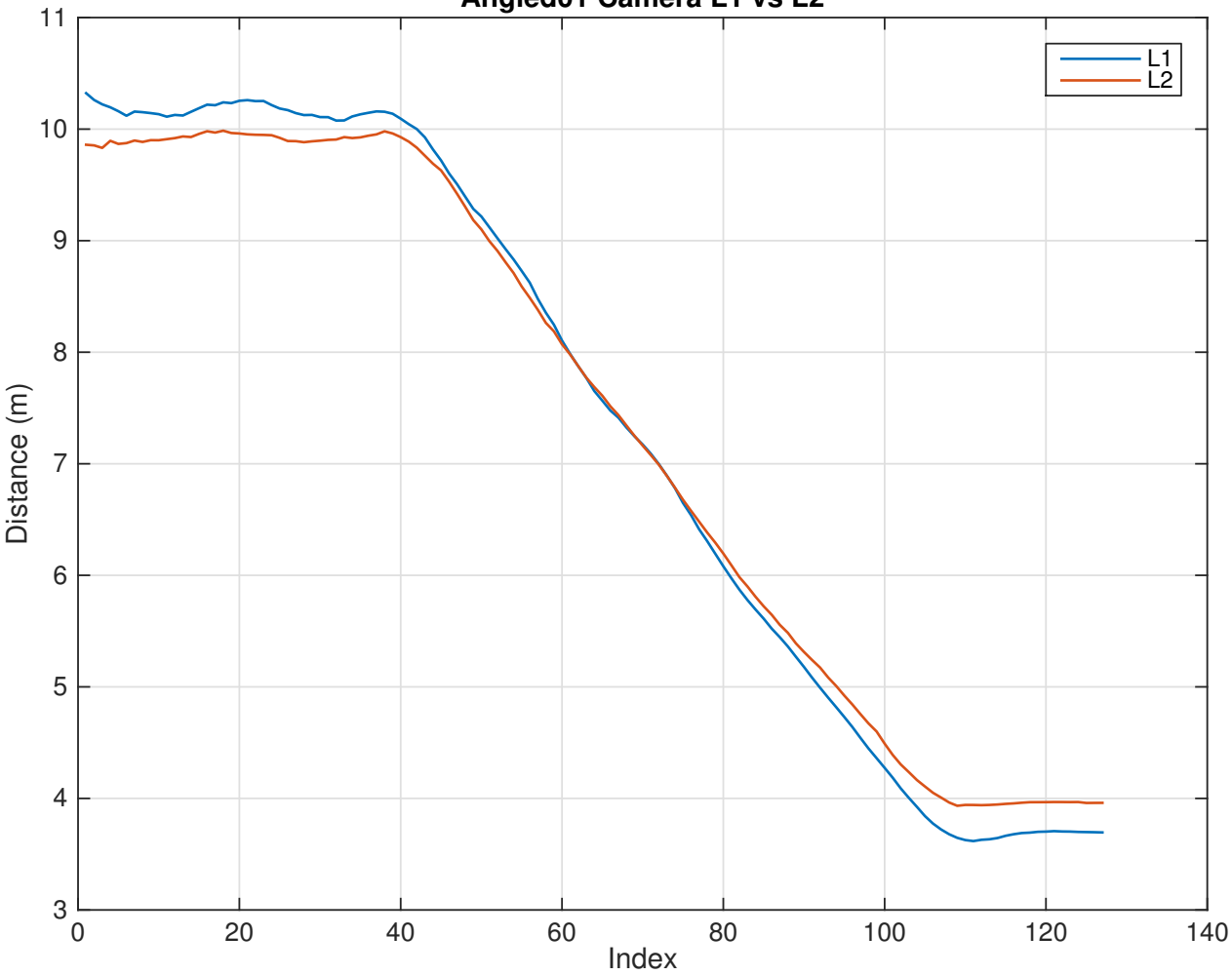
Angled01 Left_Edge vs Right_Edge



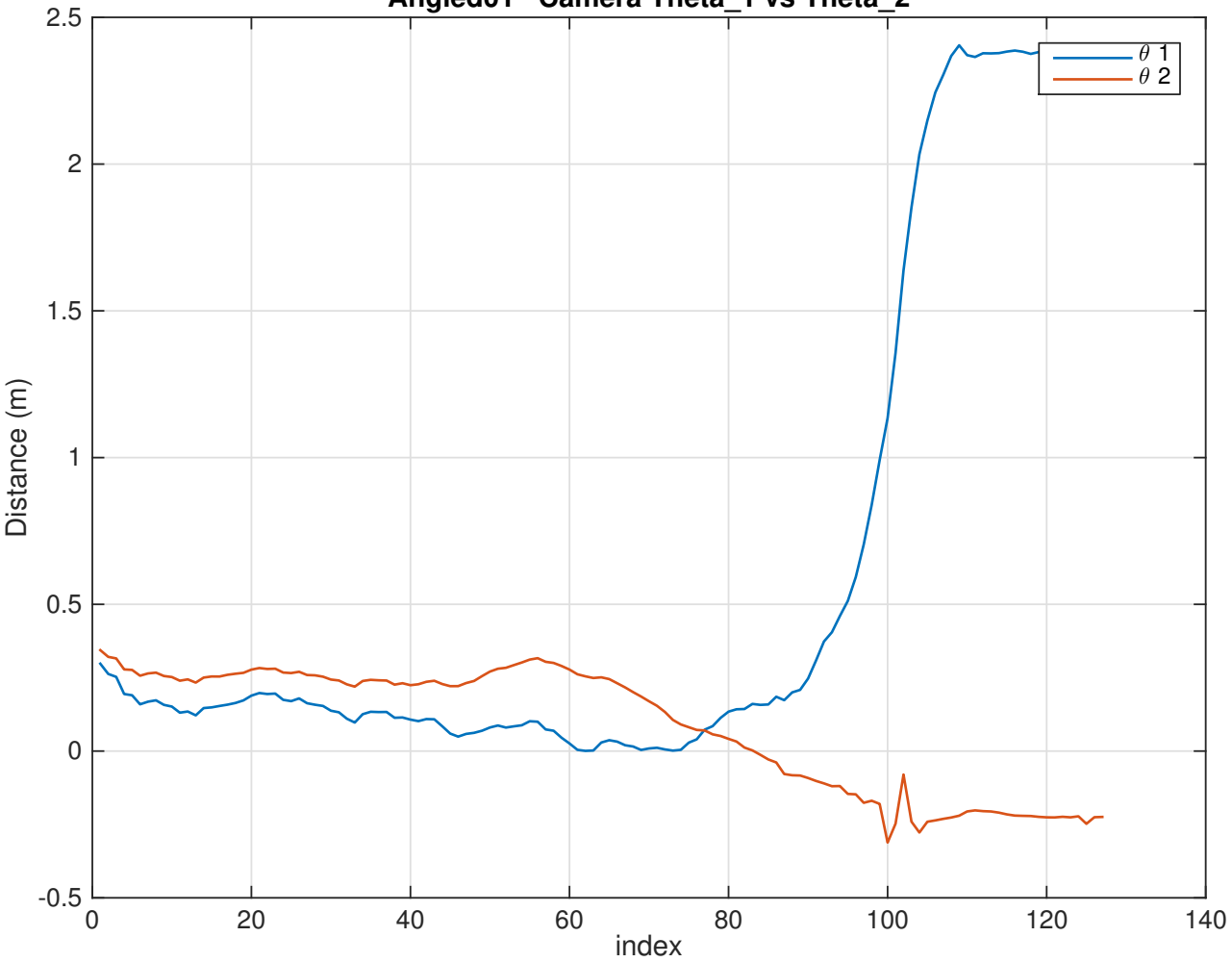
Angled01 LIDAR Distance vs Camera Center Distance



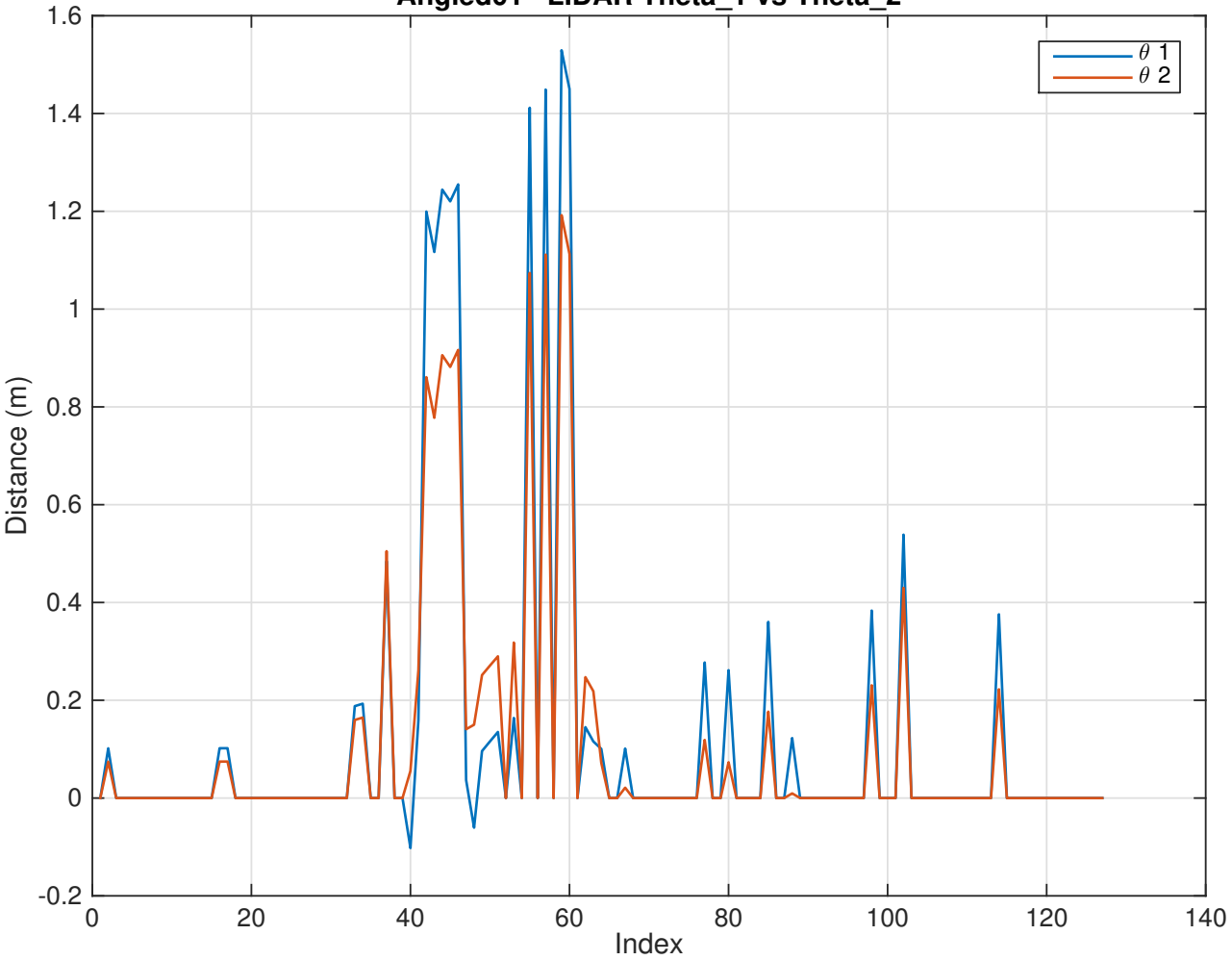
Angled01 Camera L1 vs L2



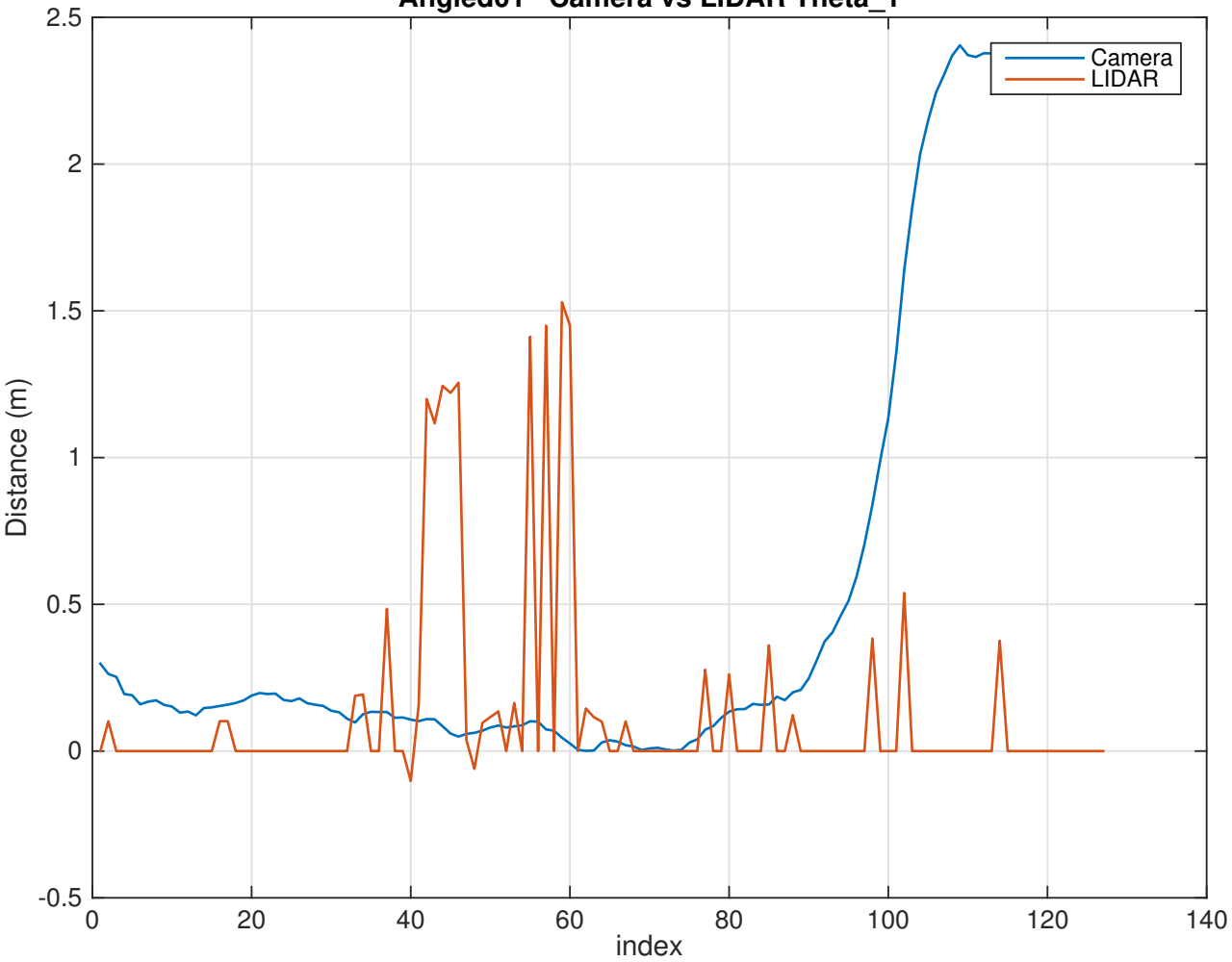
Angled01 Camera Theta_1 vs Theta_2



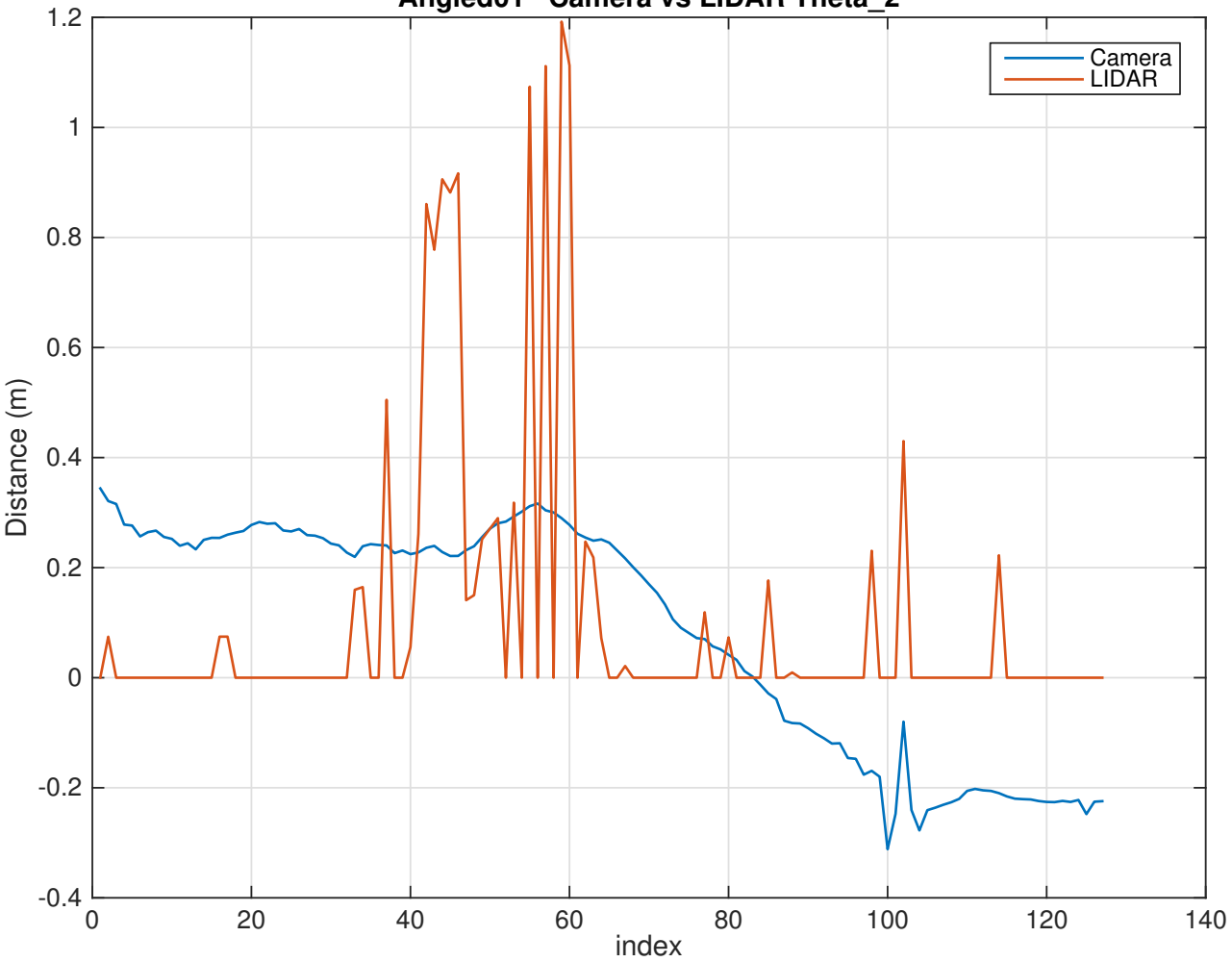
Angled01 LIDAR Theta_1 vs Theta_2



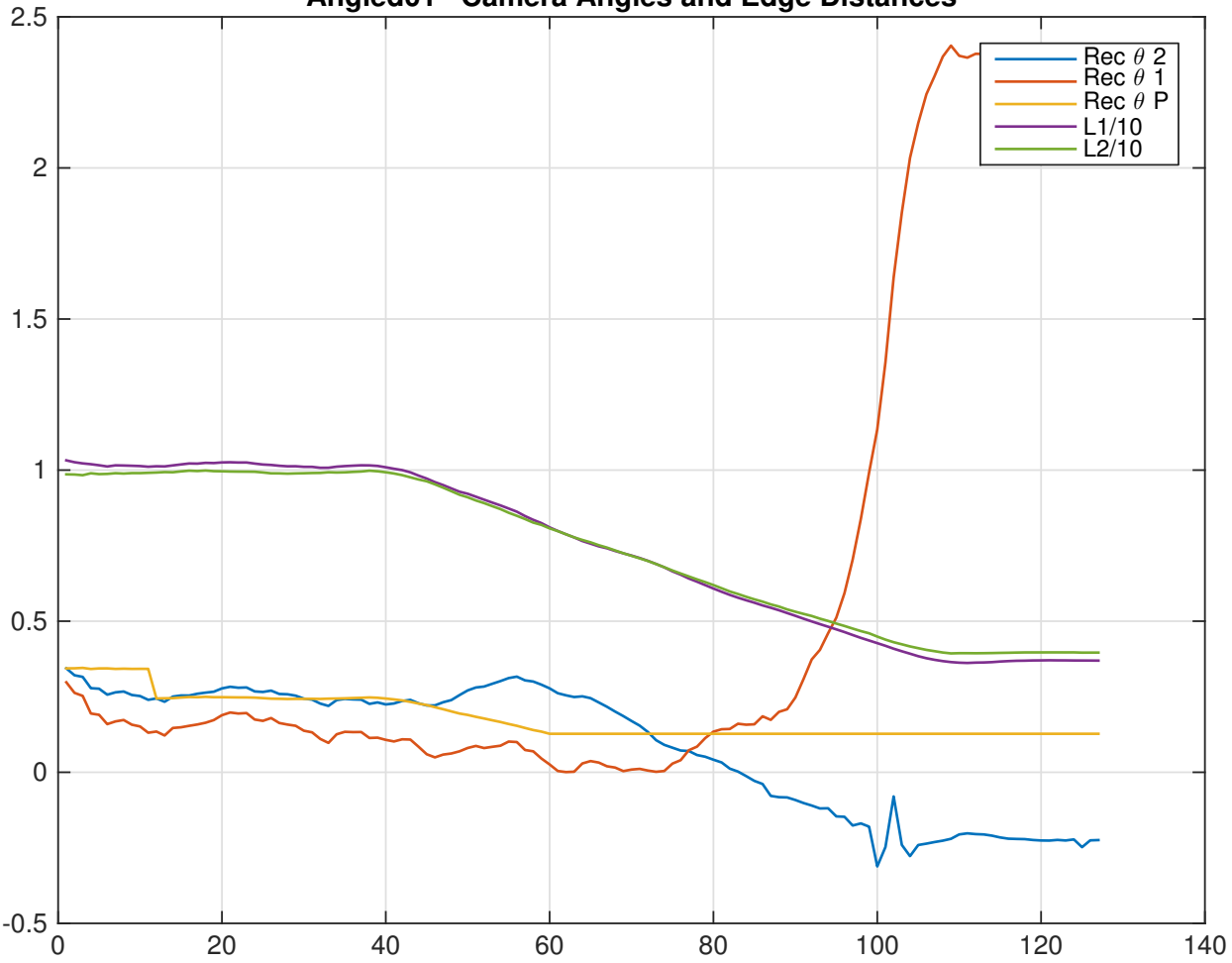
Angled01 Camera vs LIDAR Theta_1



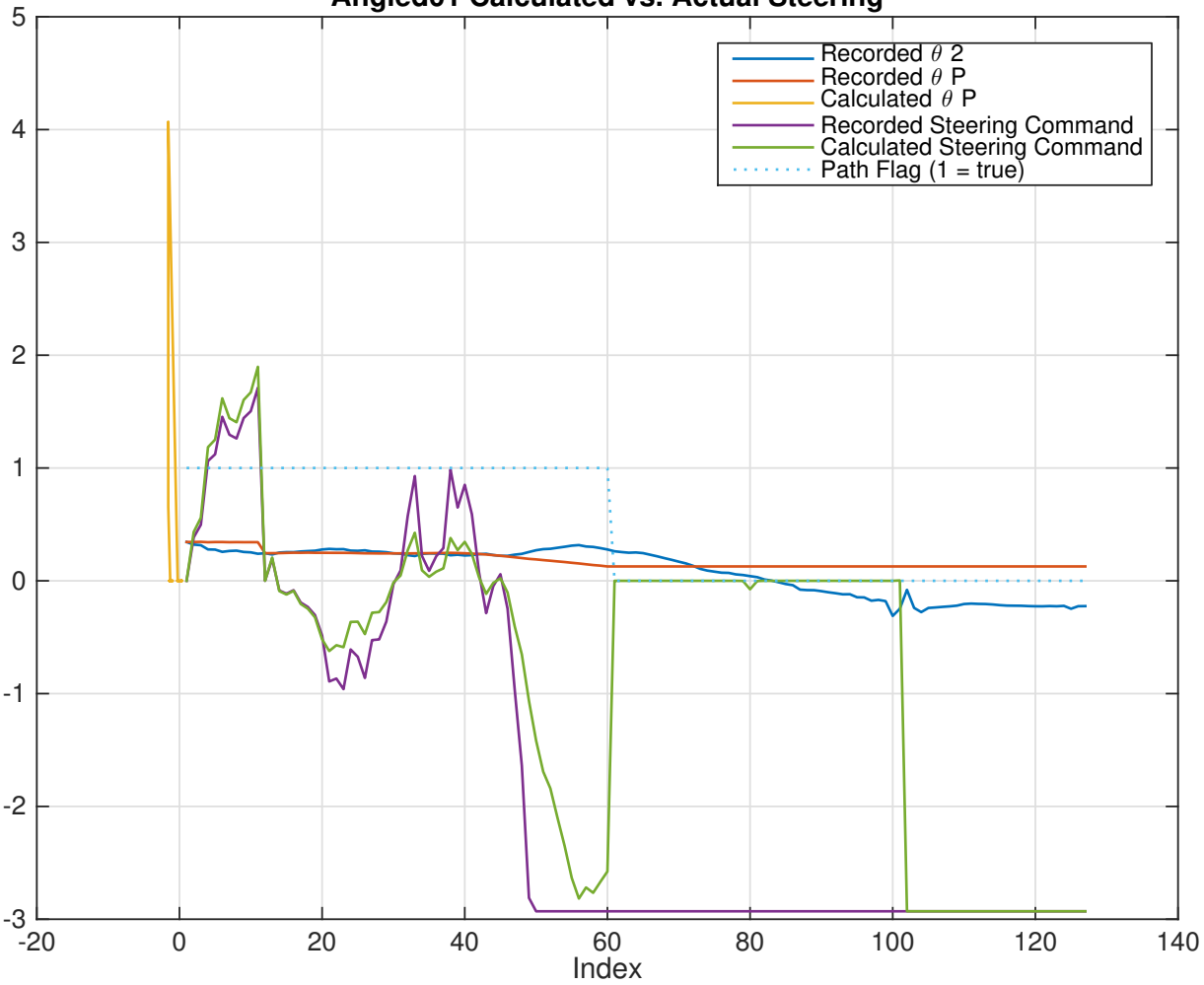
Angled01 Camera vs LIDAR Theta_2



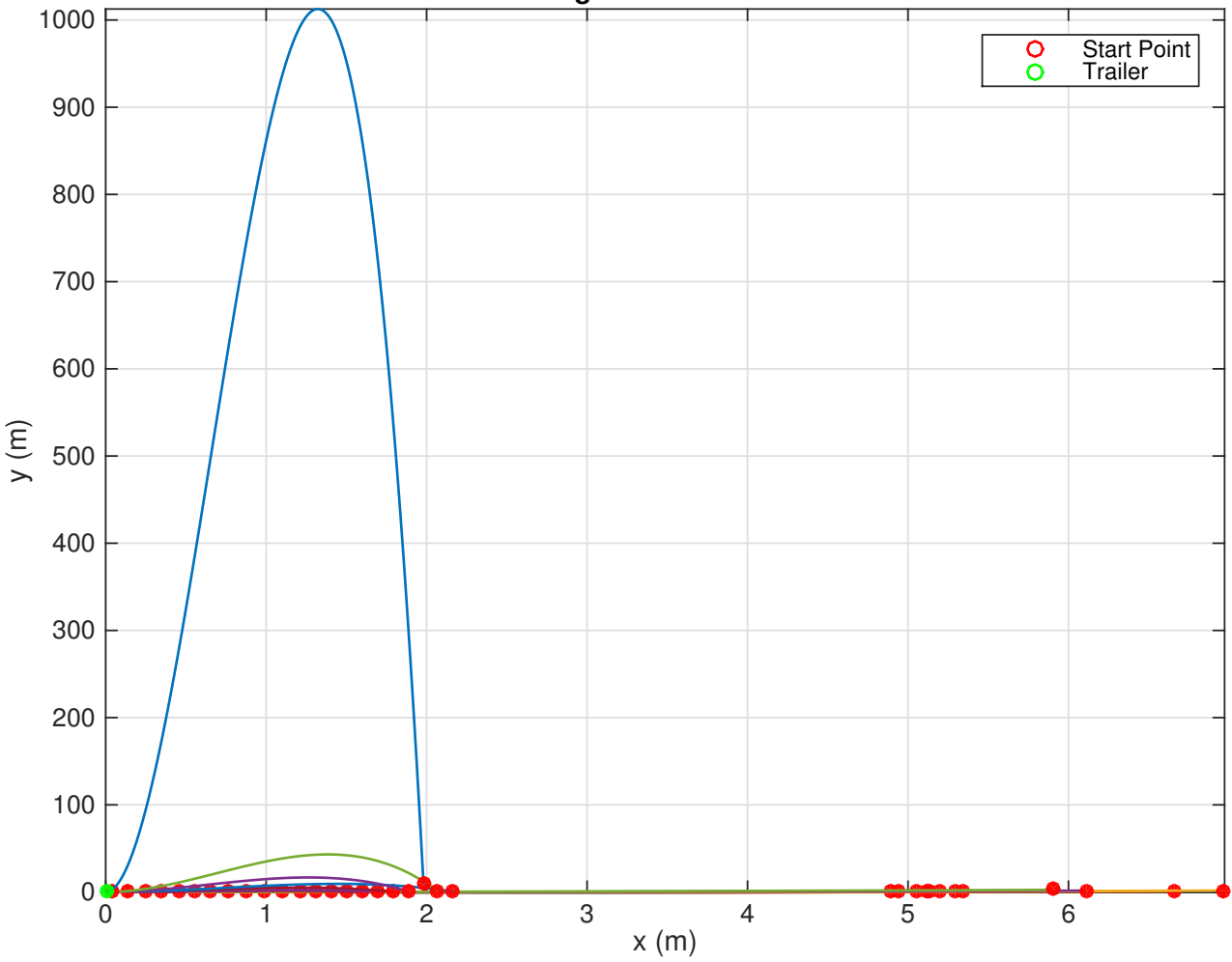
Angled01 Camera Angles and Edge Distances



Angled01 Calculated vs. Actual Steering



Angled02 All Paths



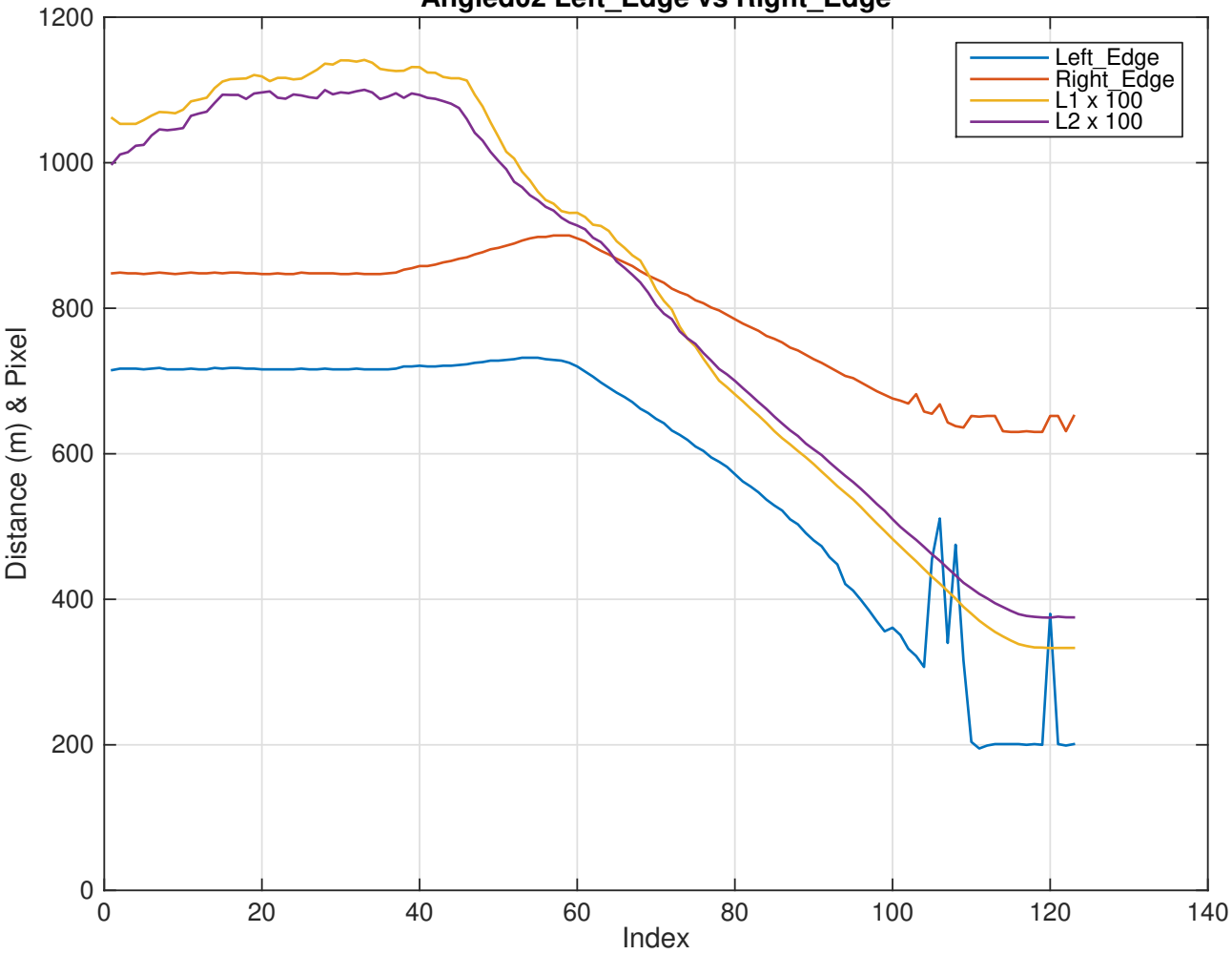
Number_Of_Unique_Paths

King_Pin_Detected

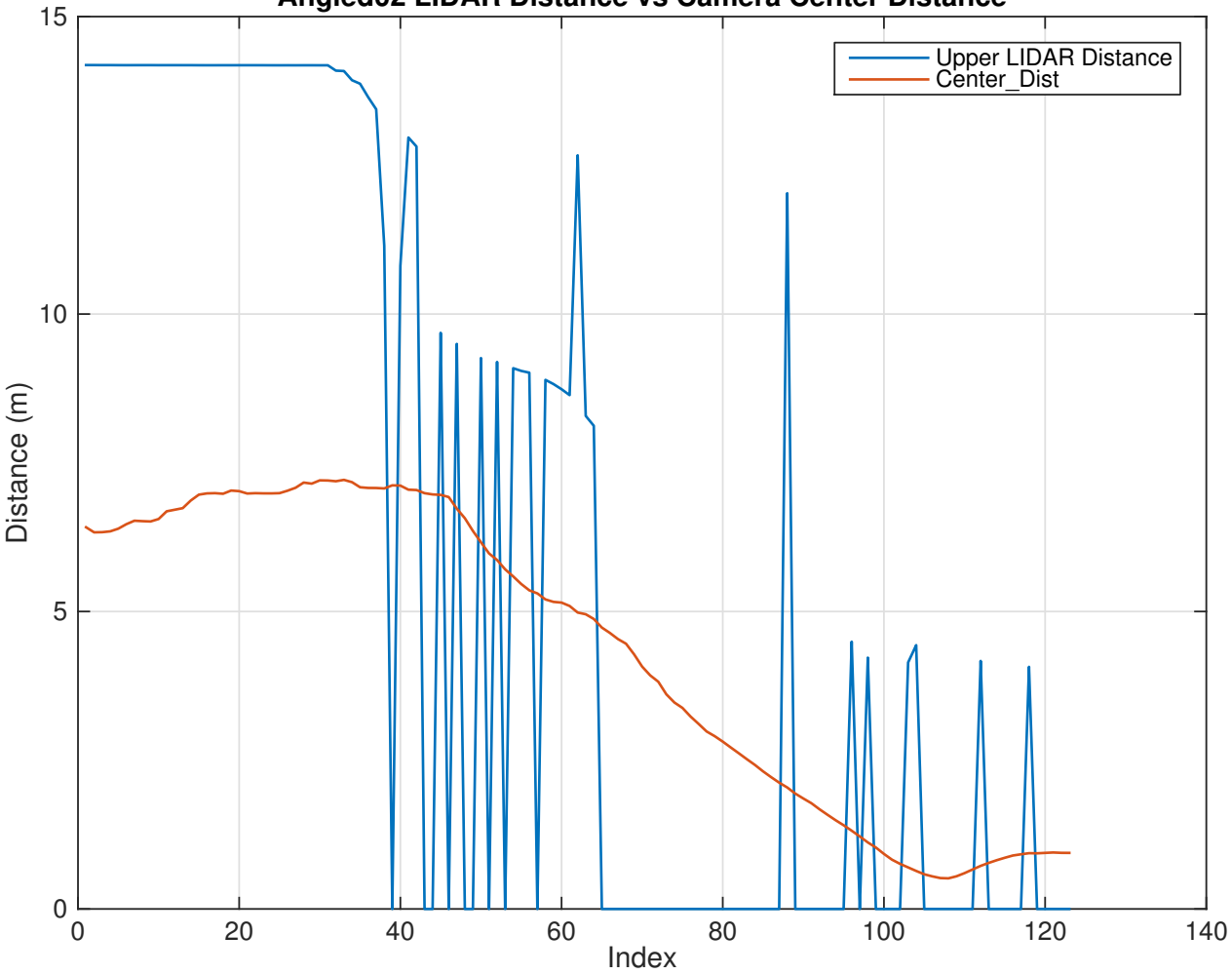
15

false

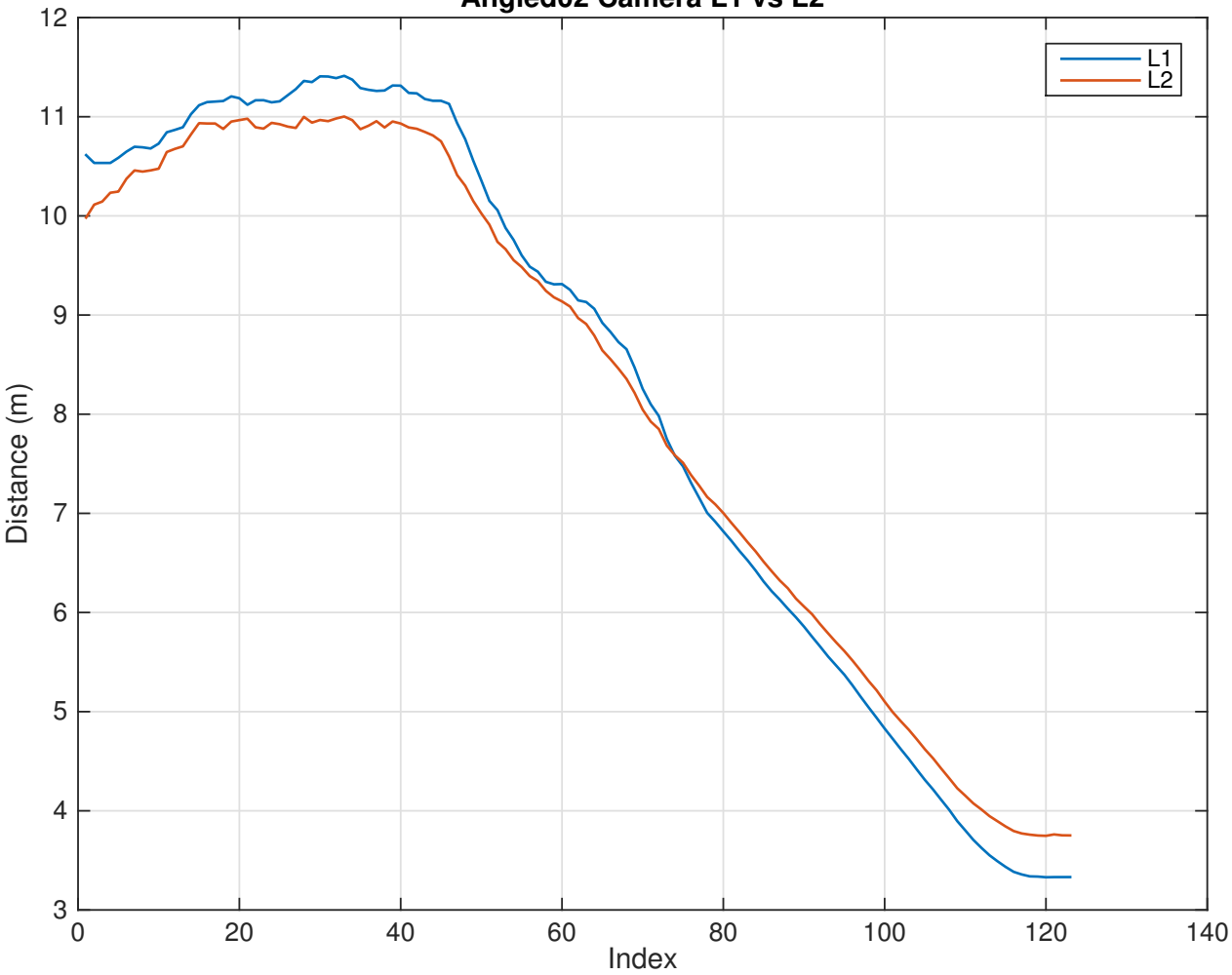
Angled02 Left_Edge vs Right_Edge



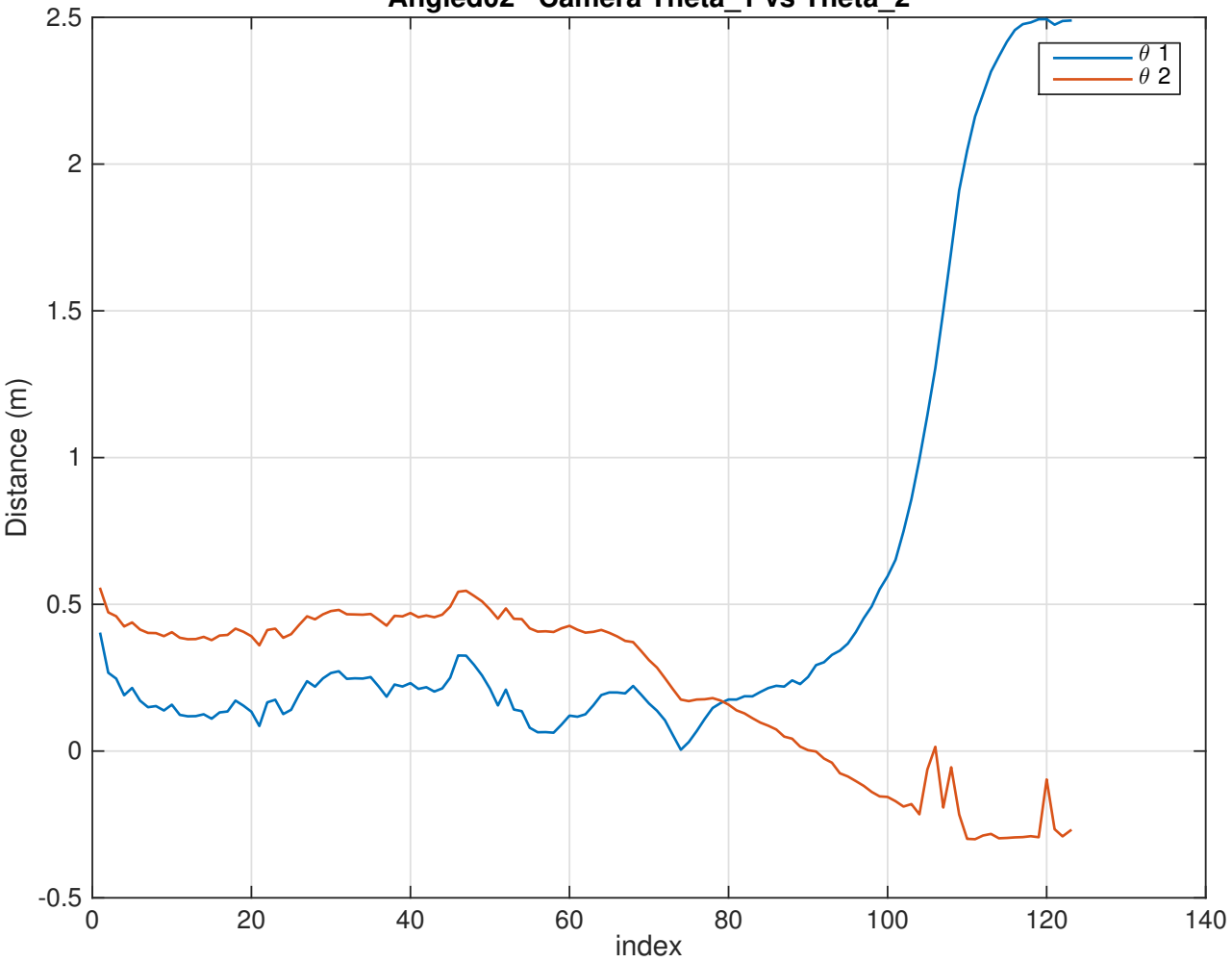
Angled02 LIDAR Distance vs Camera Center Distance



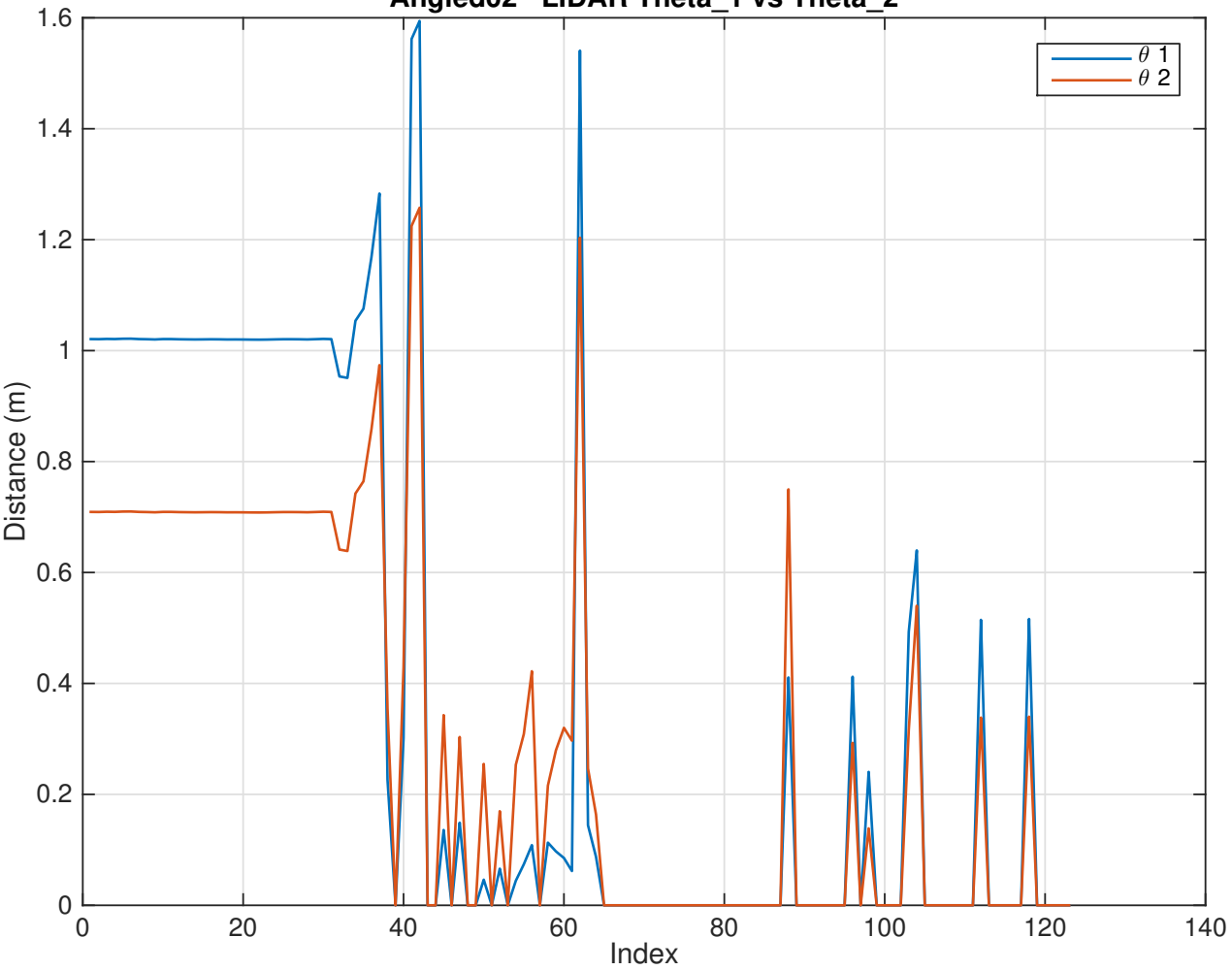
Angled02 Camera L1 vs L2



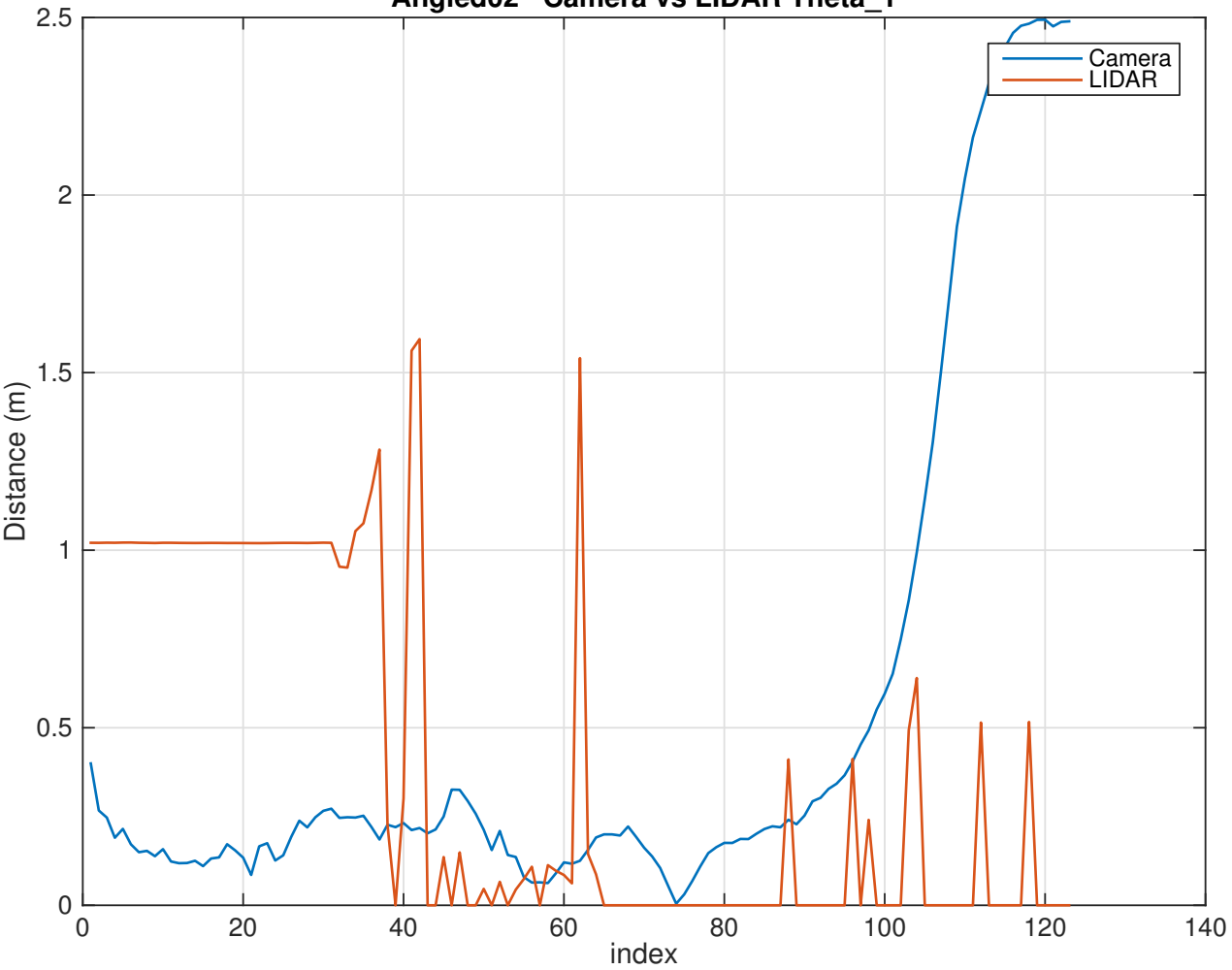
Angled02 Camera Theta_1 vs Theta_2



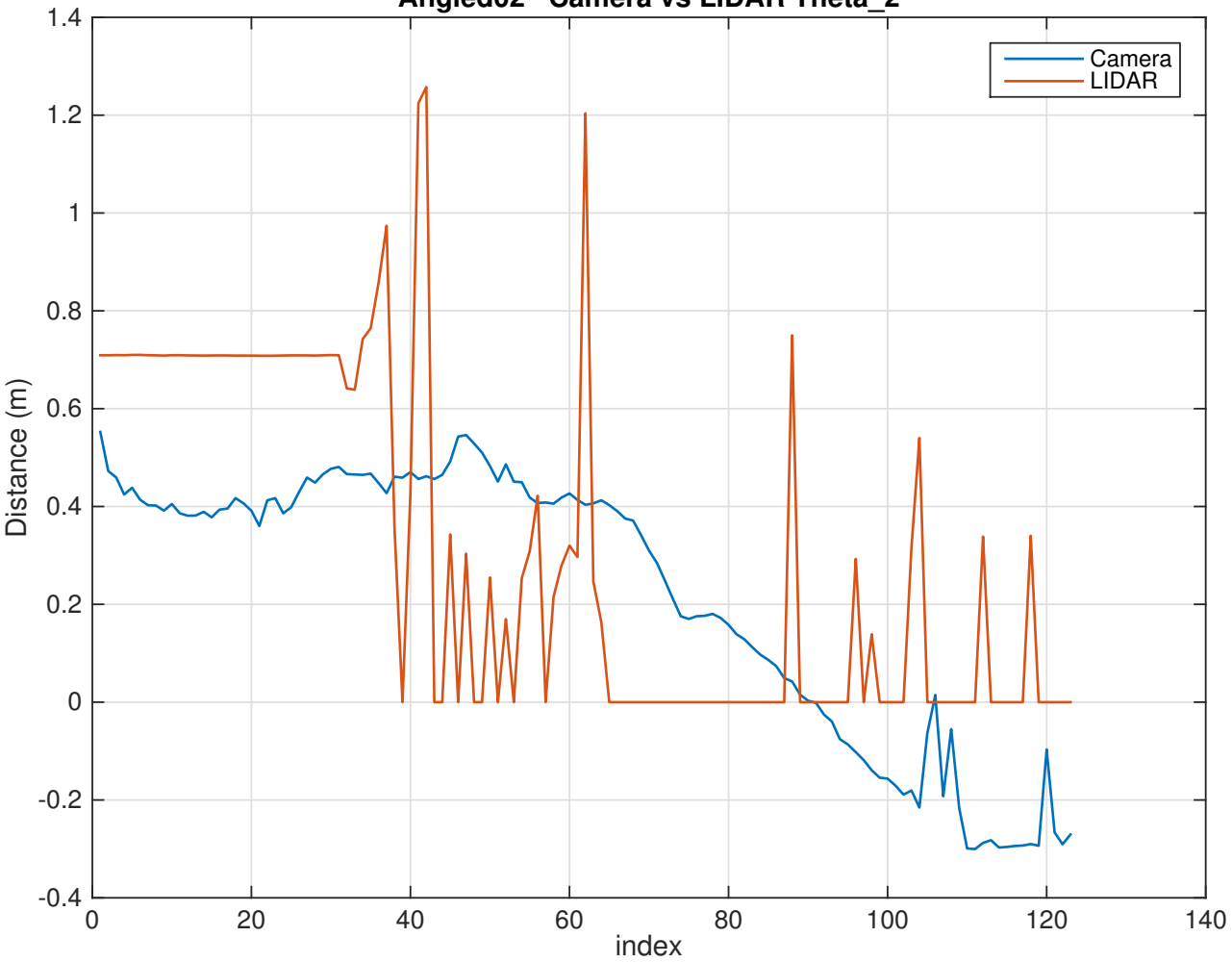
Angled02 LIDAR Theta_1 vs Theta_2



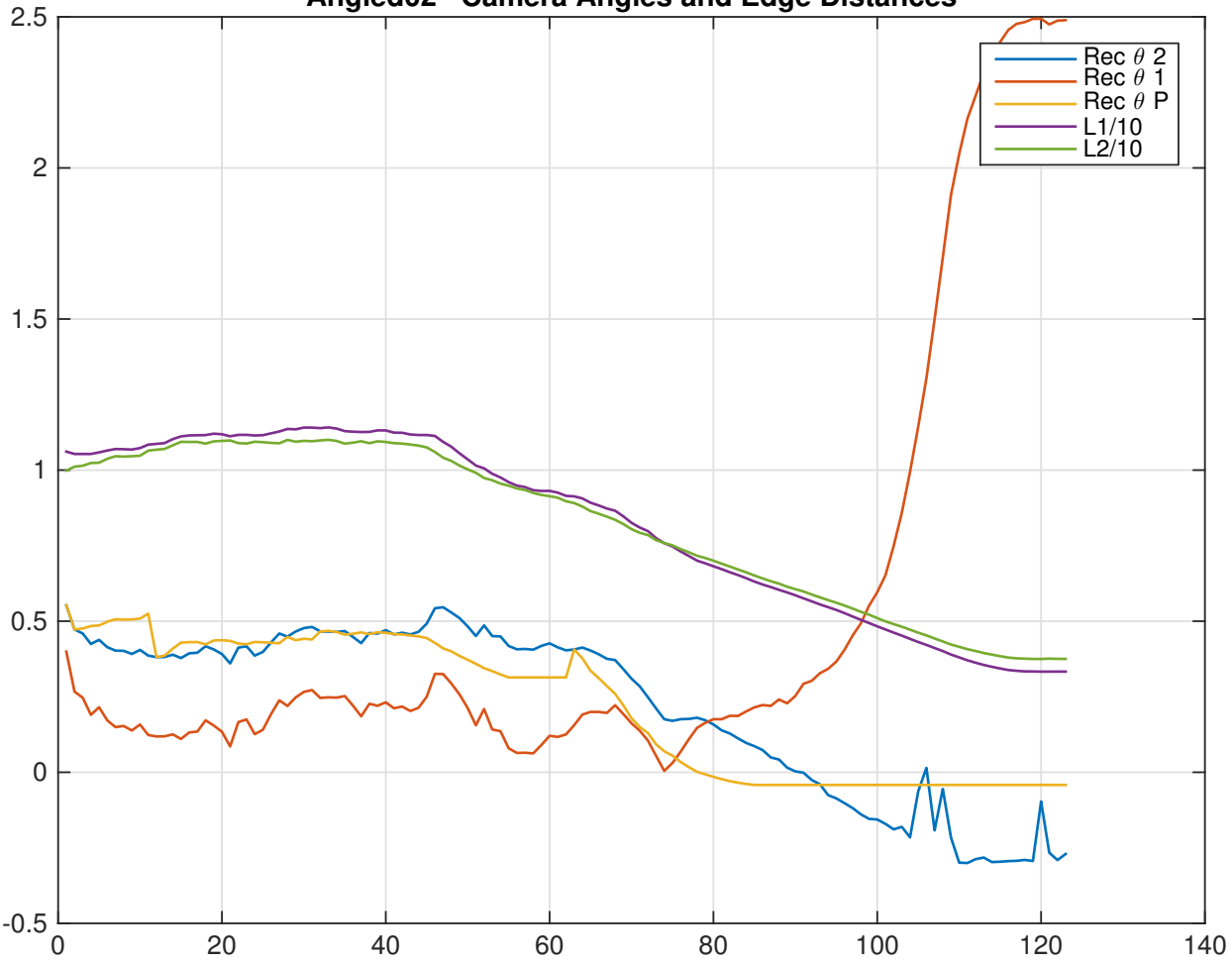
Angled02 Camera vs LIDAR Theta_1



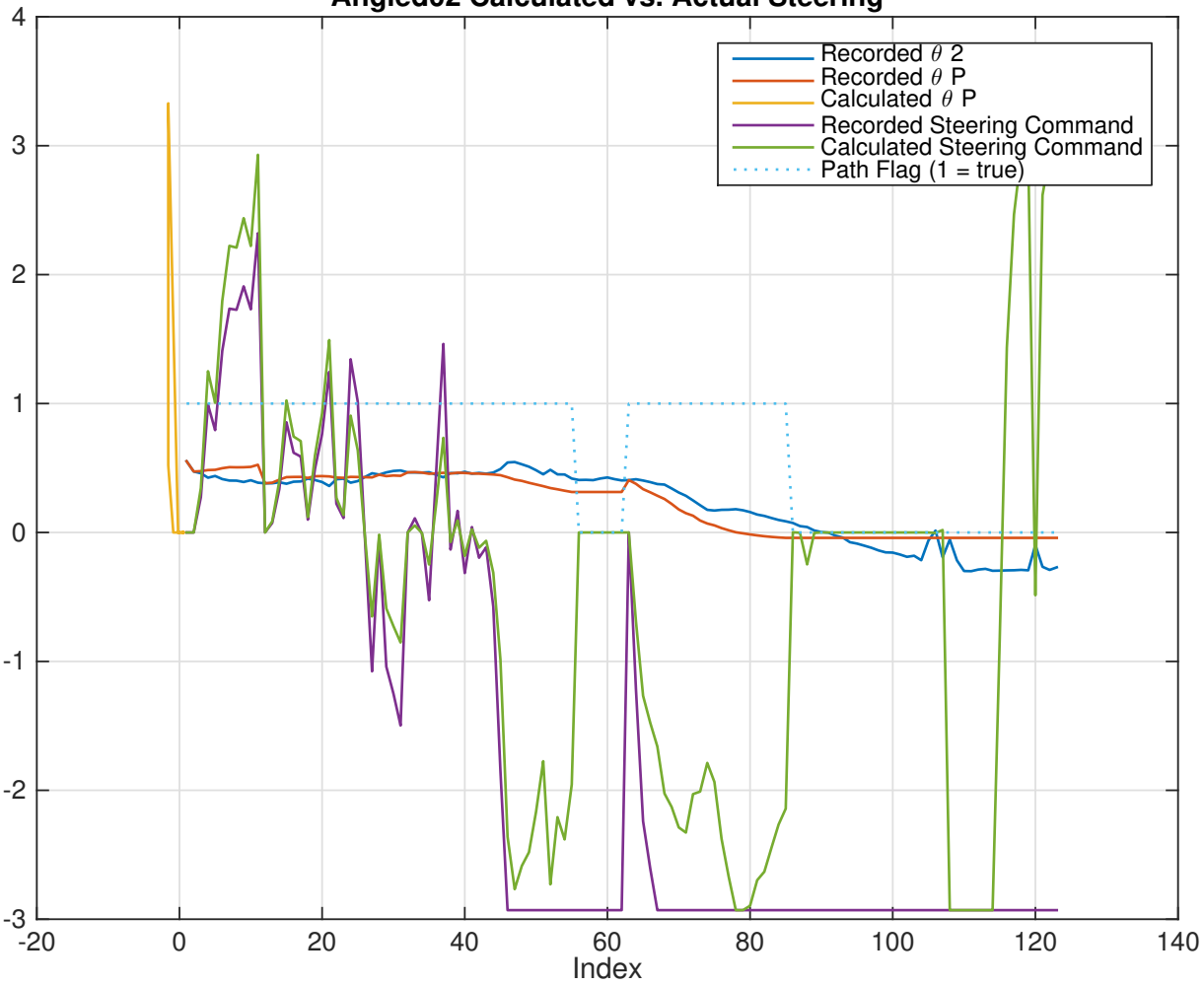
Angled02 Camera vs LIDAR Theta_2



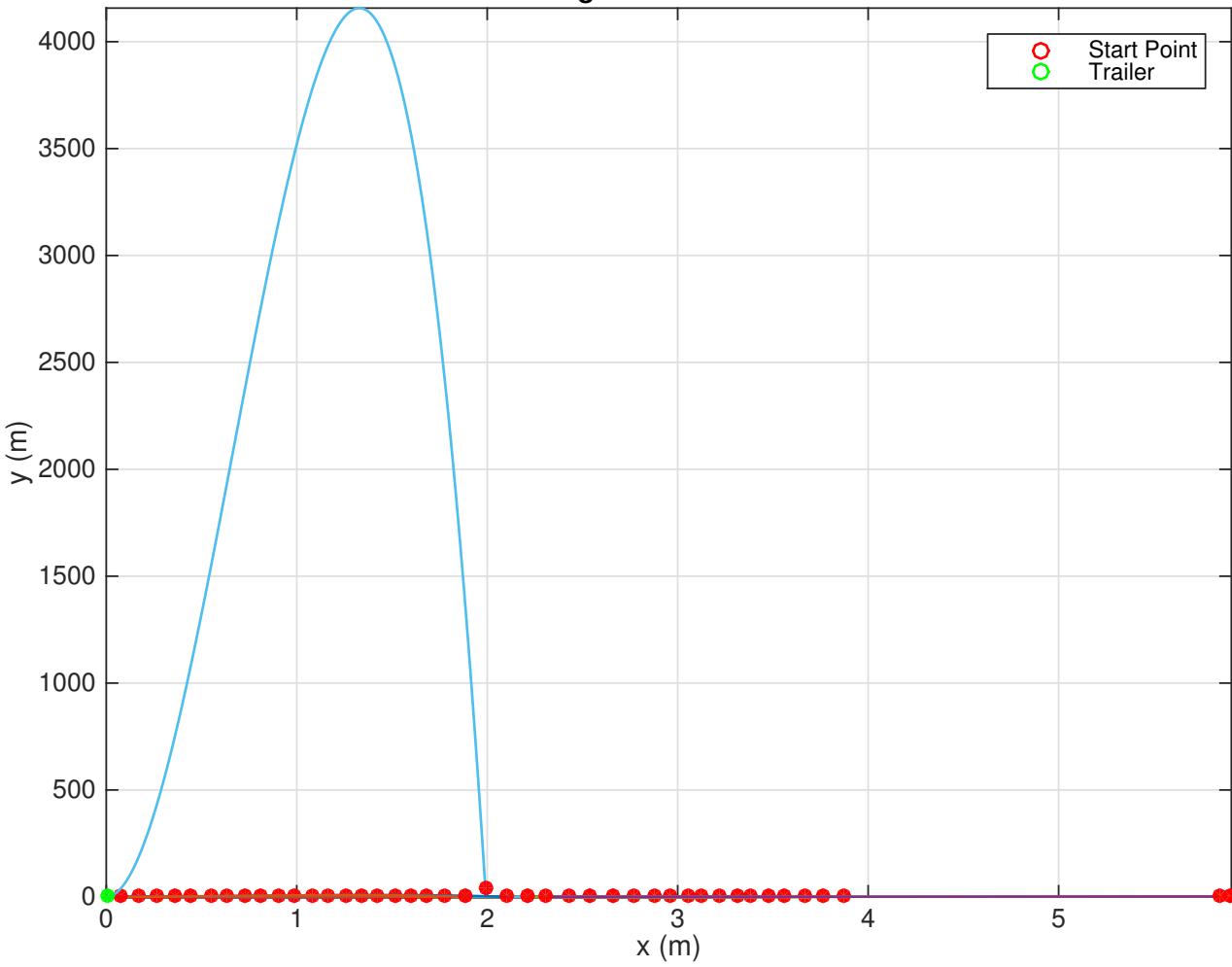
Angled02 Camera Angles and Edge Distances



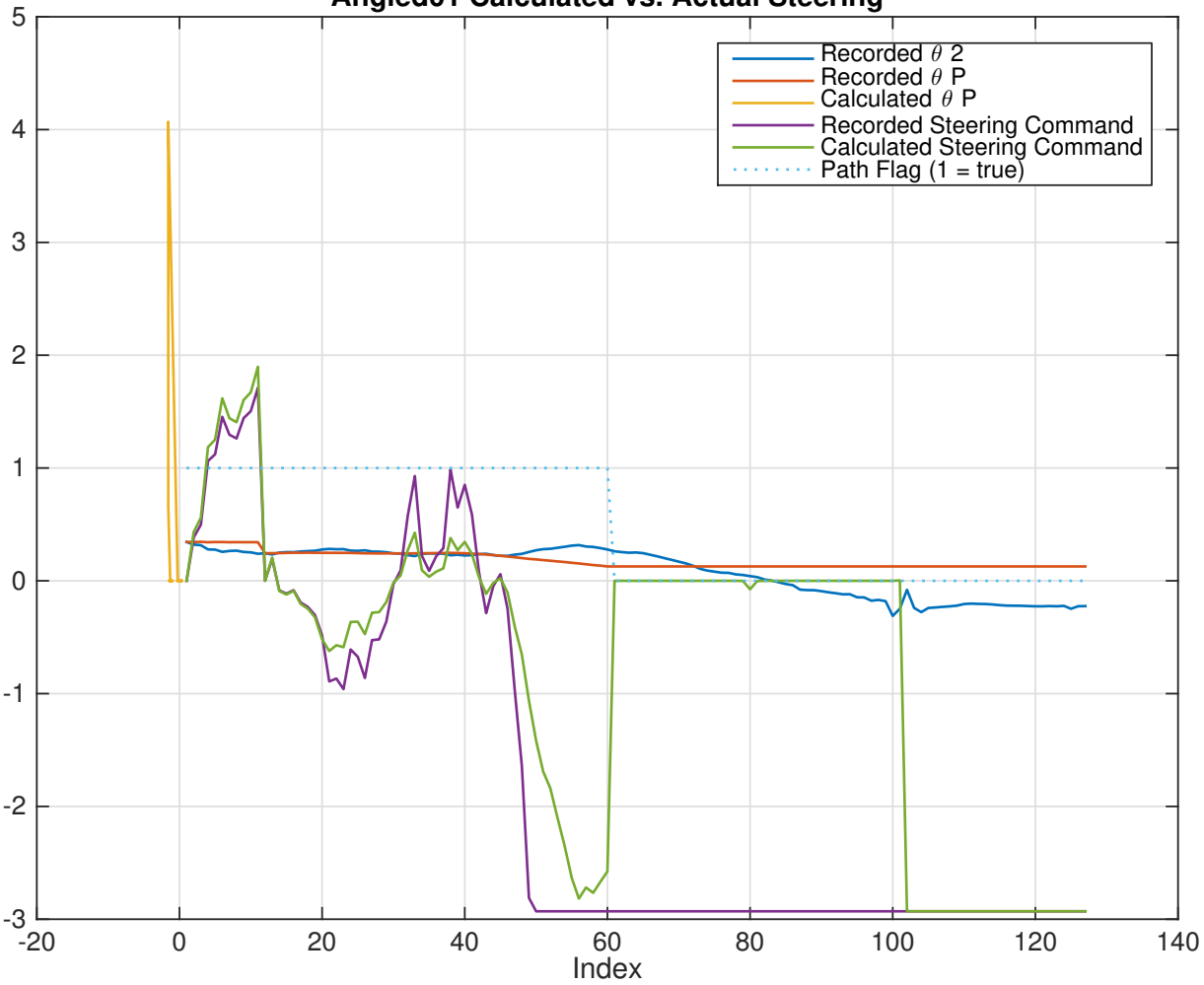
Angled02 Calculated vs. Actual Steering



Angled01 All Paths



Angled01 Calculated vs. Actual Steering



Angled01 Calculated vs. Actual Steering

