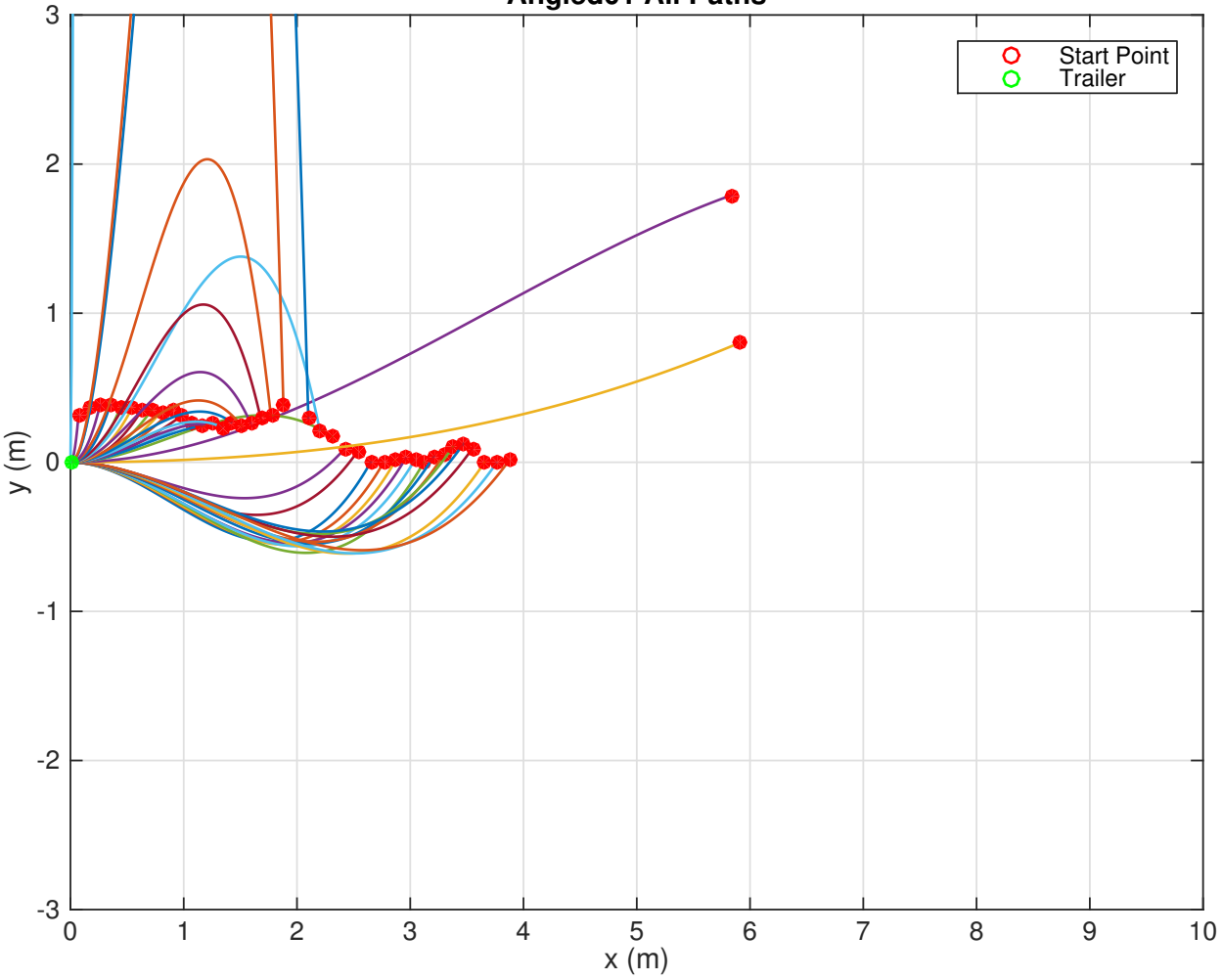


Angled01 All Paths



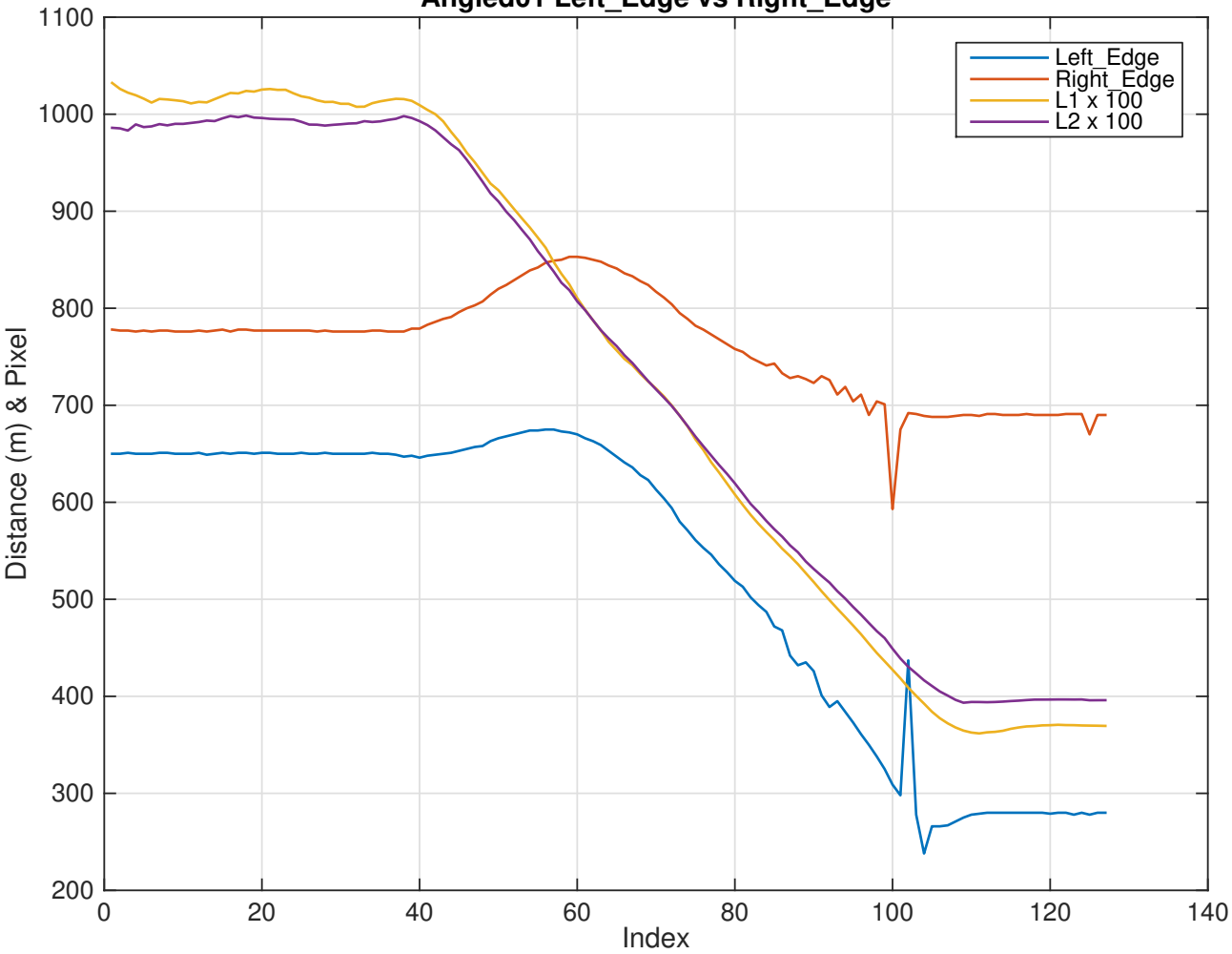
Number\_Of\_Unique\_Paths

King\_Pin\_Detected

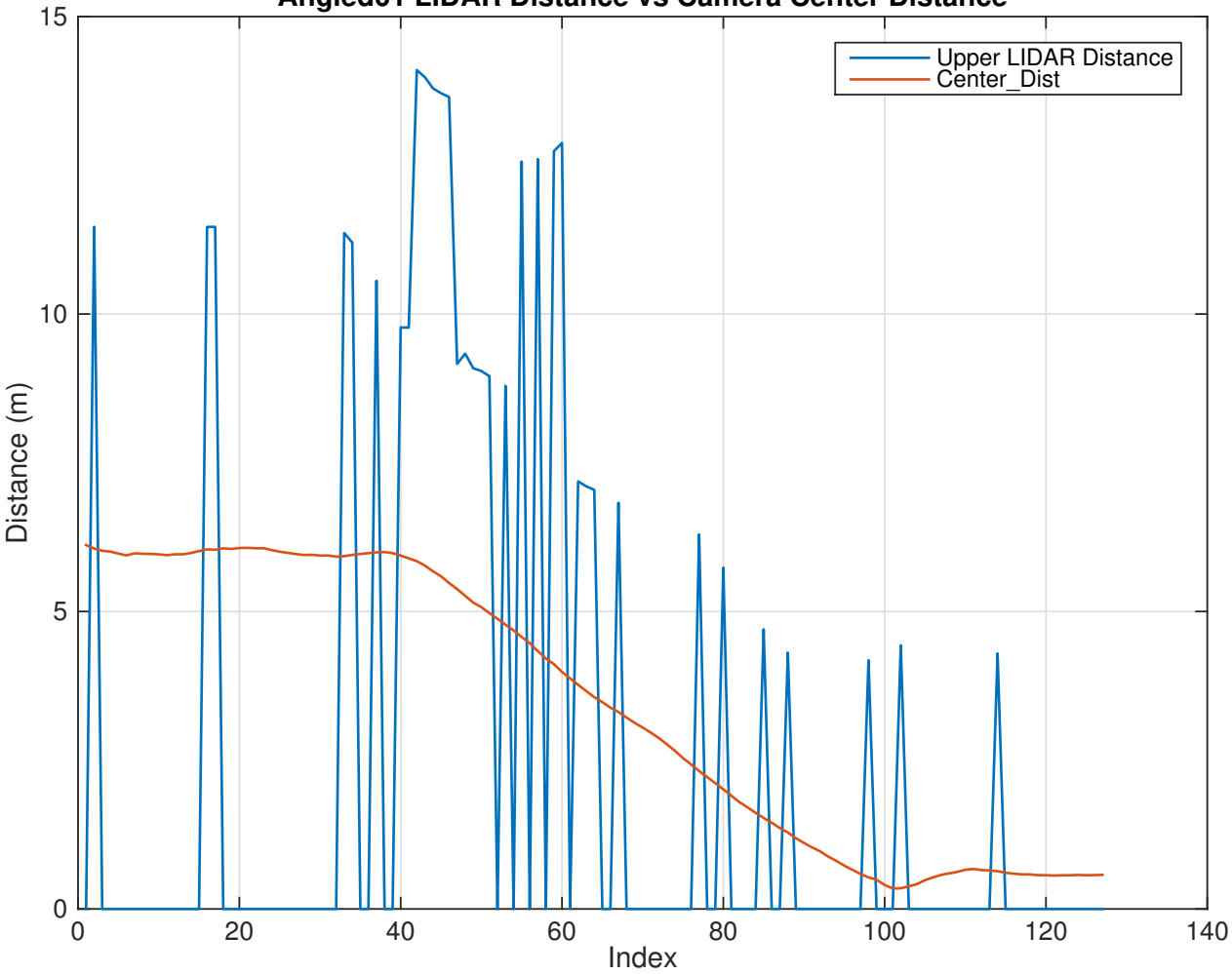
22

false

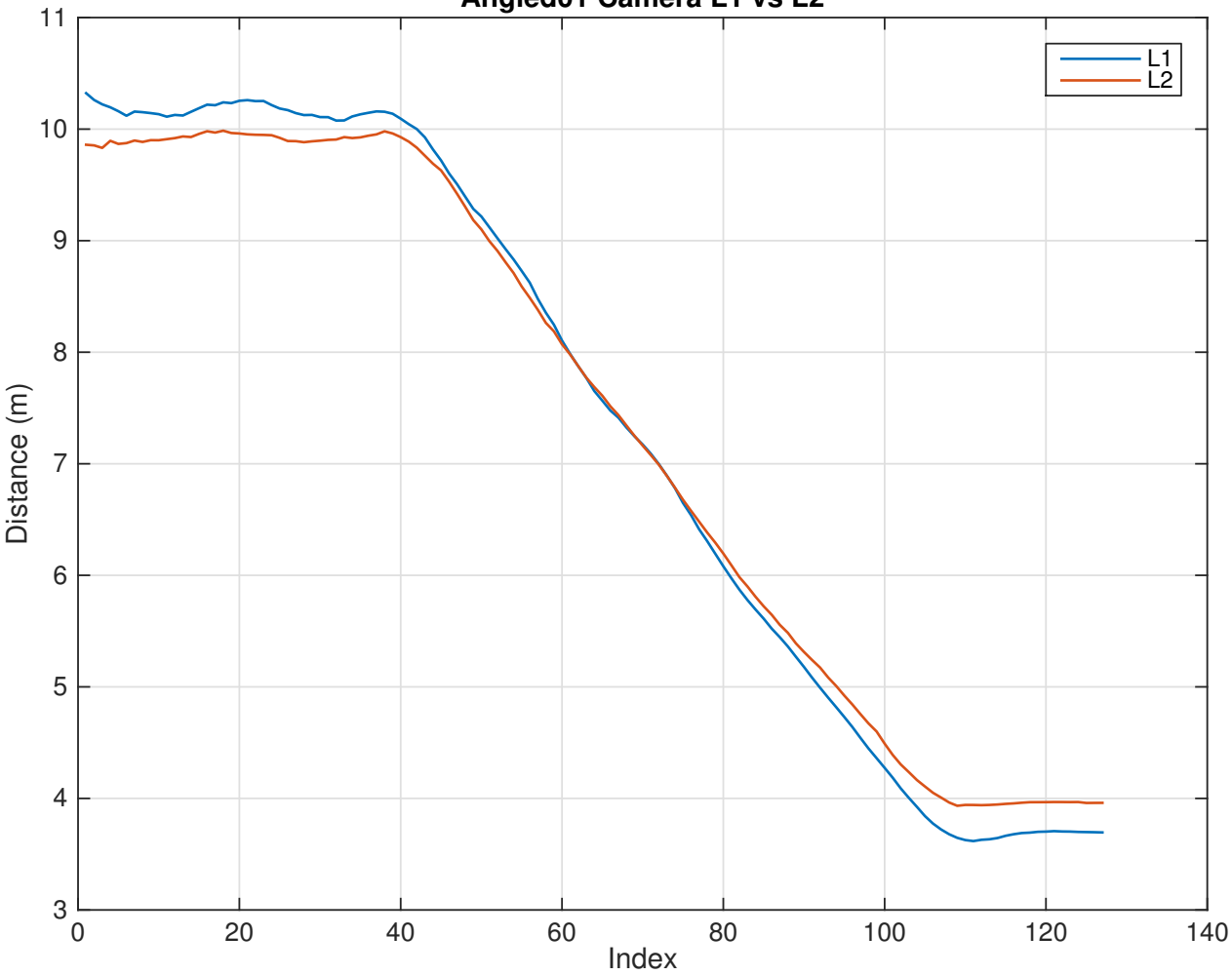
# Angled01 Left\_Edge vs Right\_Edge



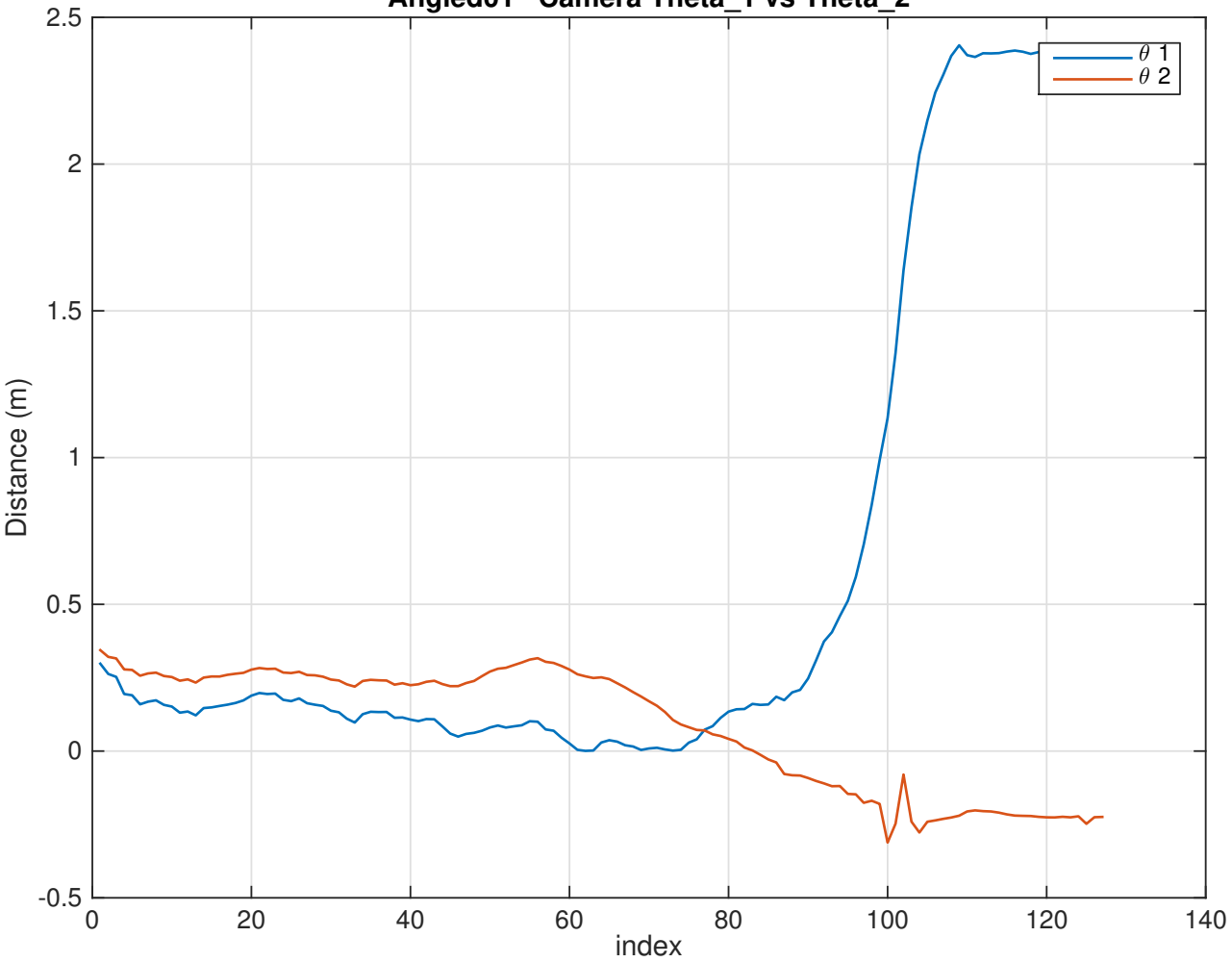
Angled01 LIDAR Distance vs Camera Center Distance



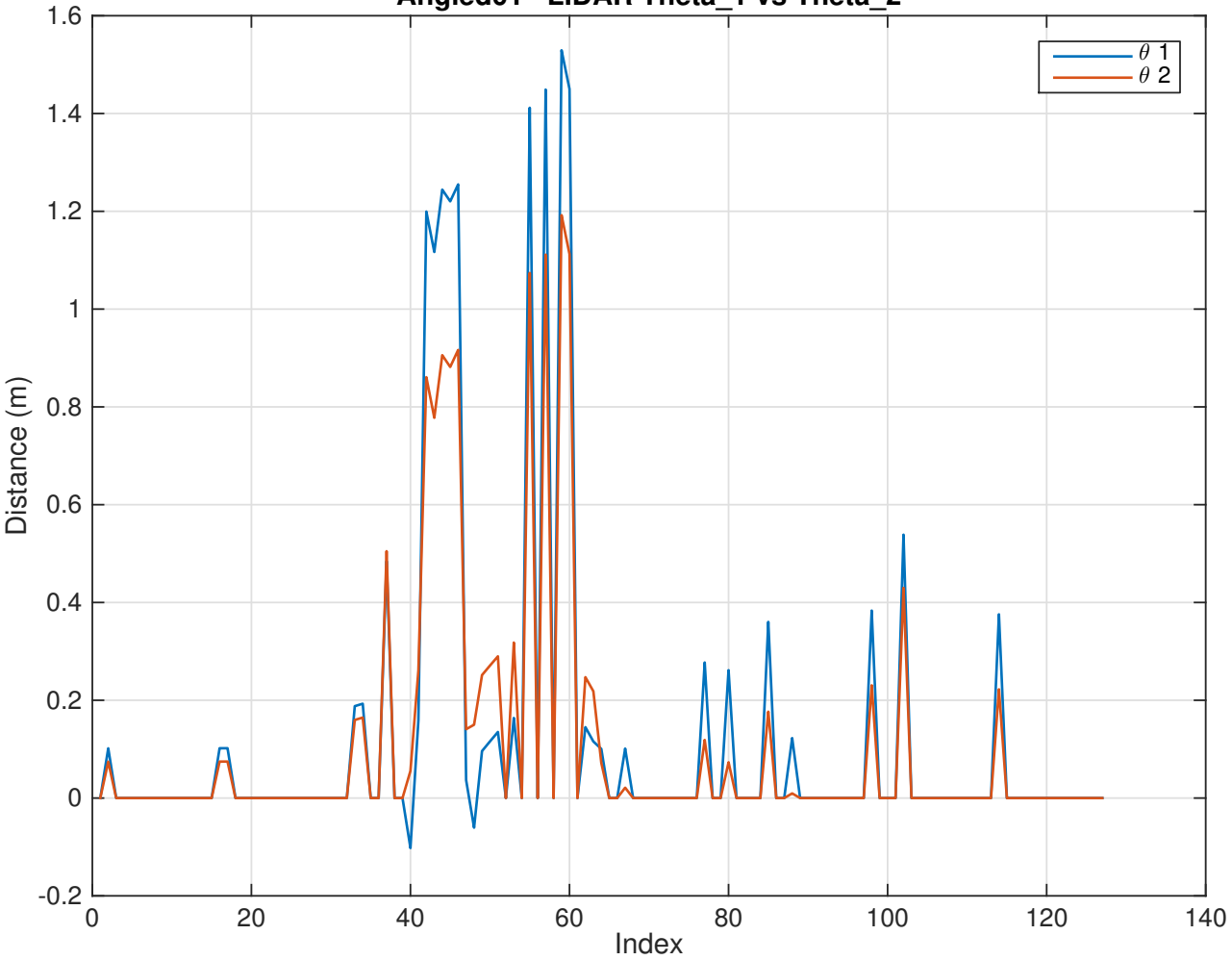
Angled01 Camera L1 vs L2



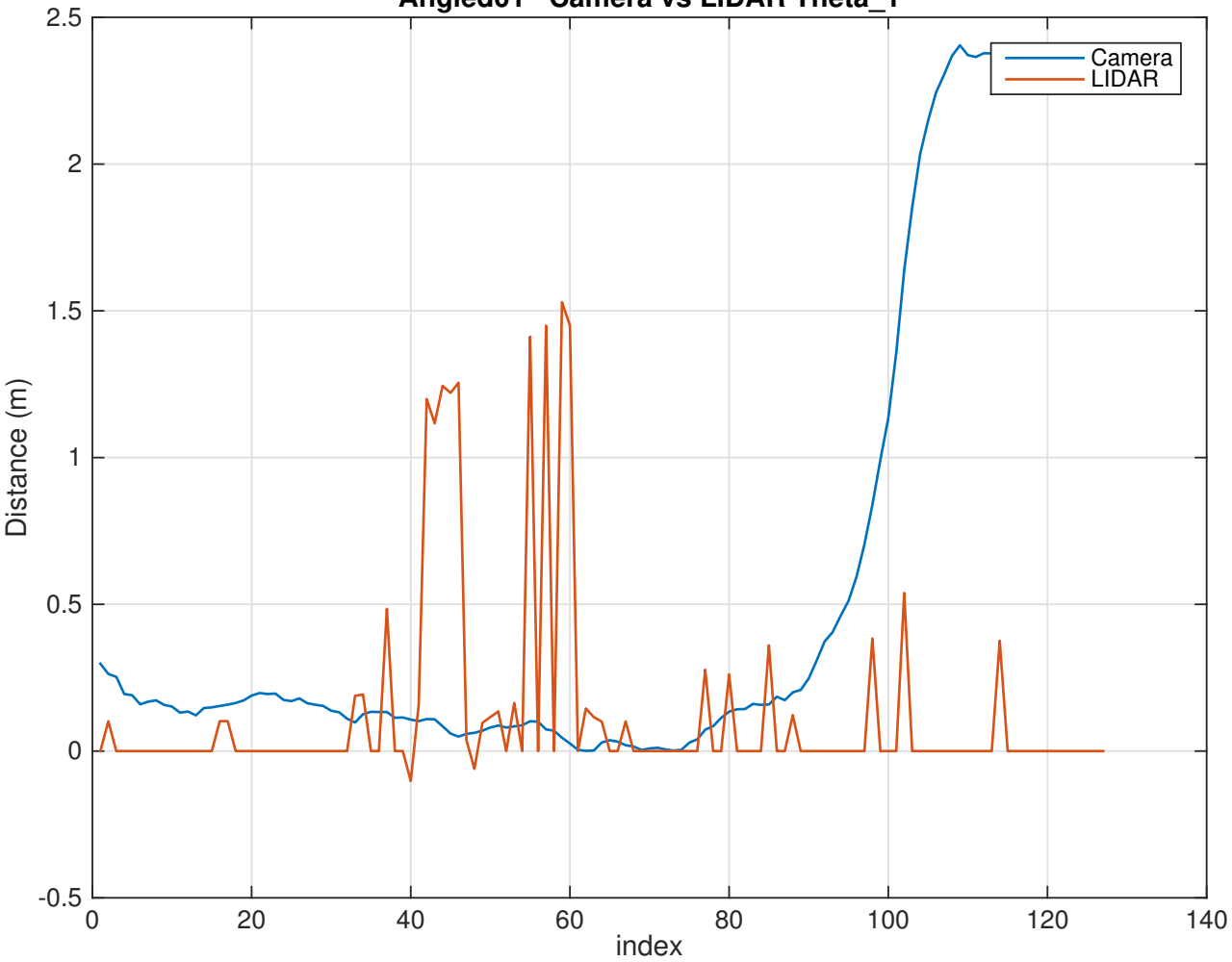
Angled01 Camera Theta\_1 vs Theta\_2



Angled01 LIDAR Theta\_1 vs Theta\_2

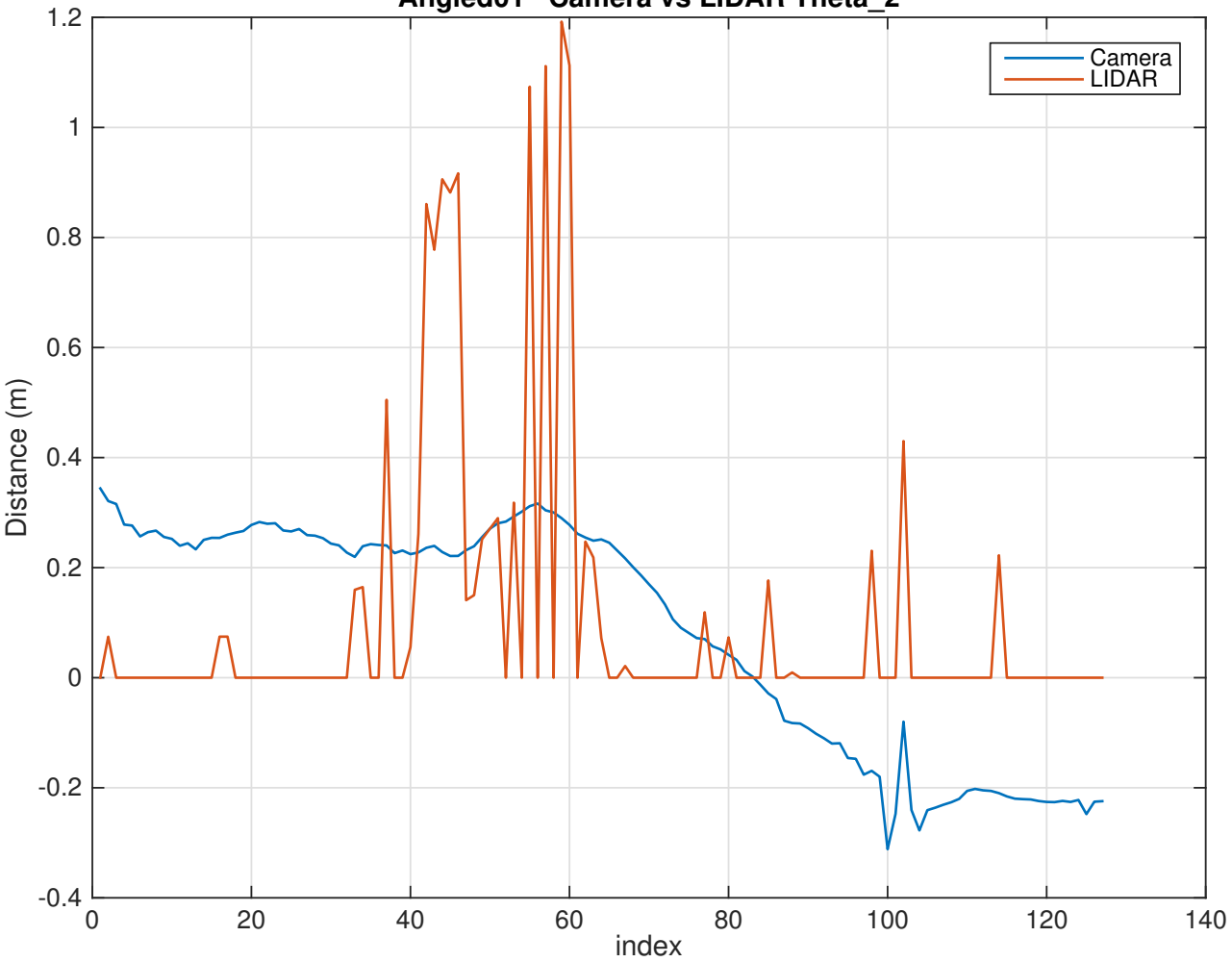


Angled01 Camera vs LIDAR Theta\_1

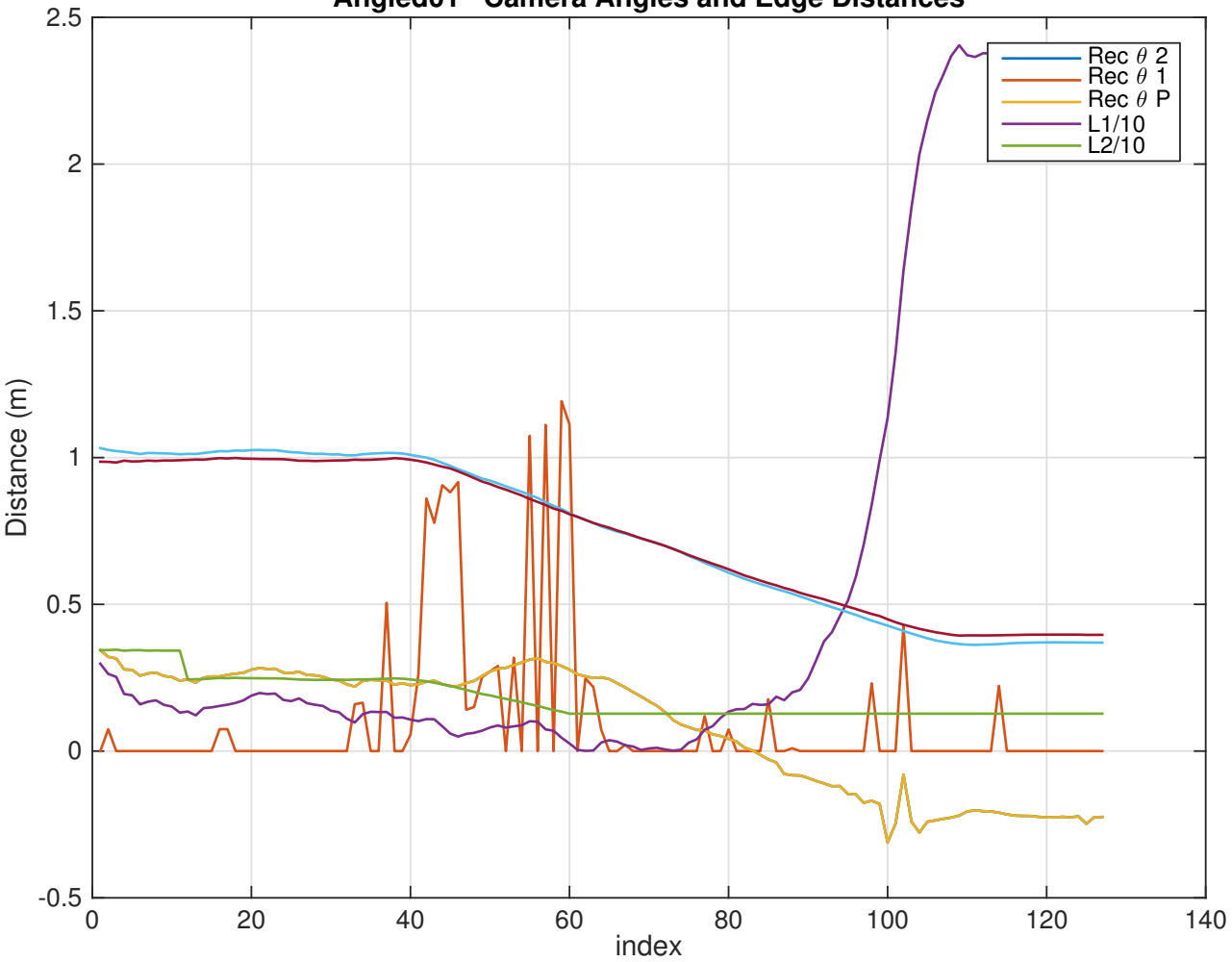




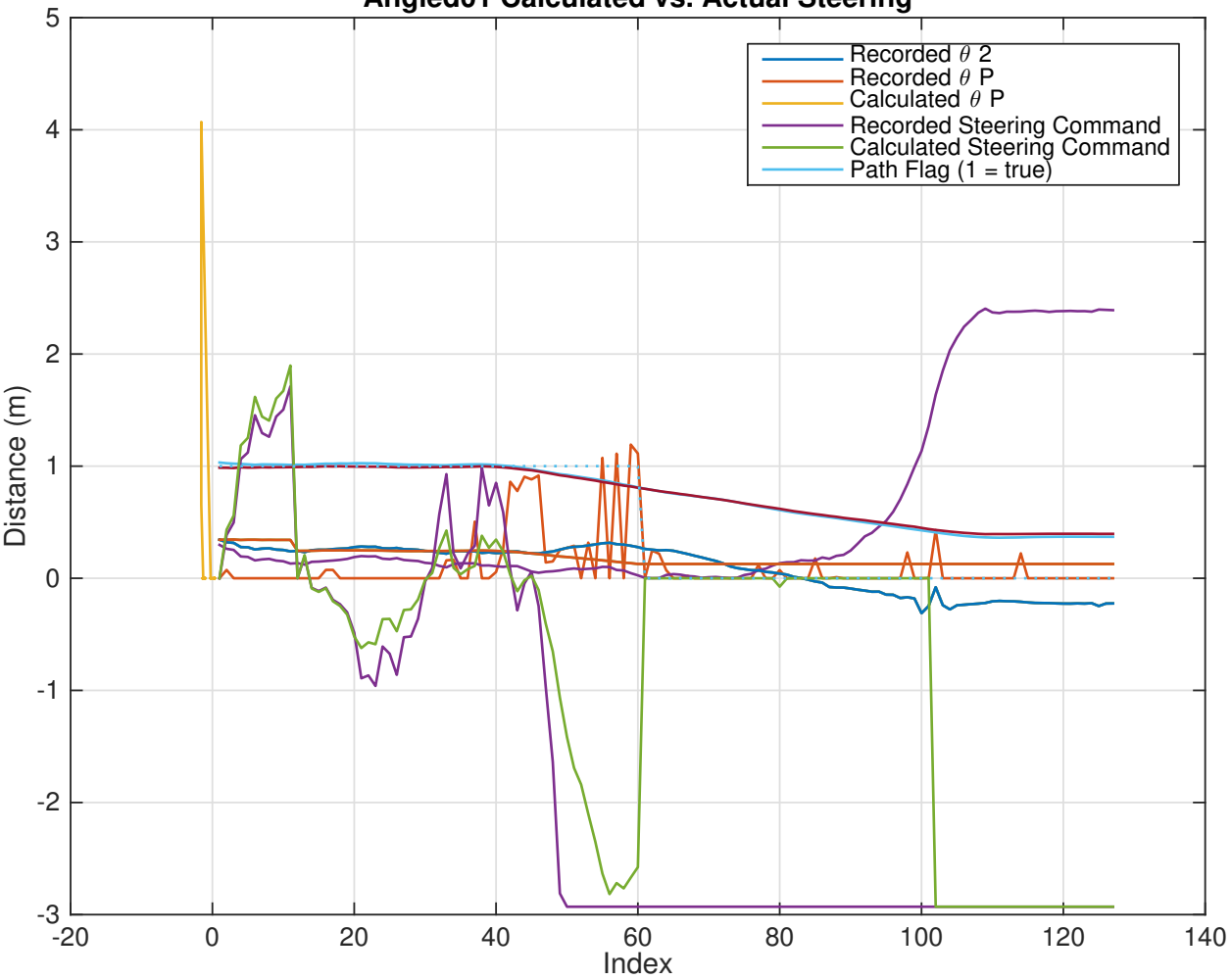
Angled01 Camera vs LIDAR Theta\_2



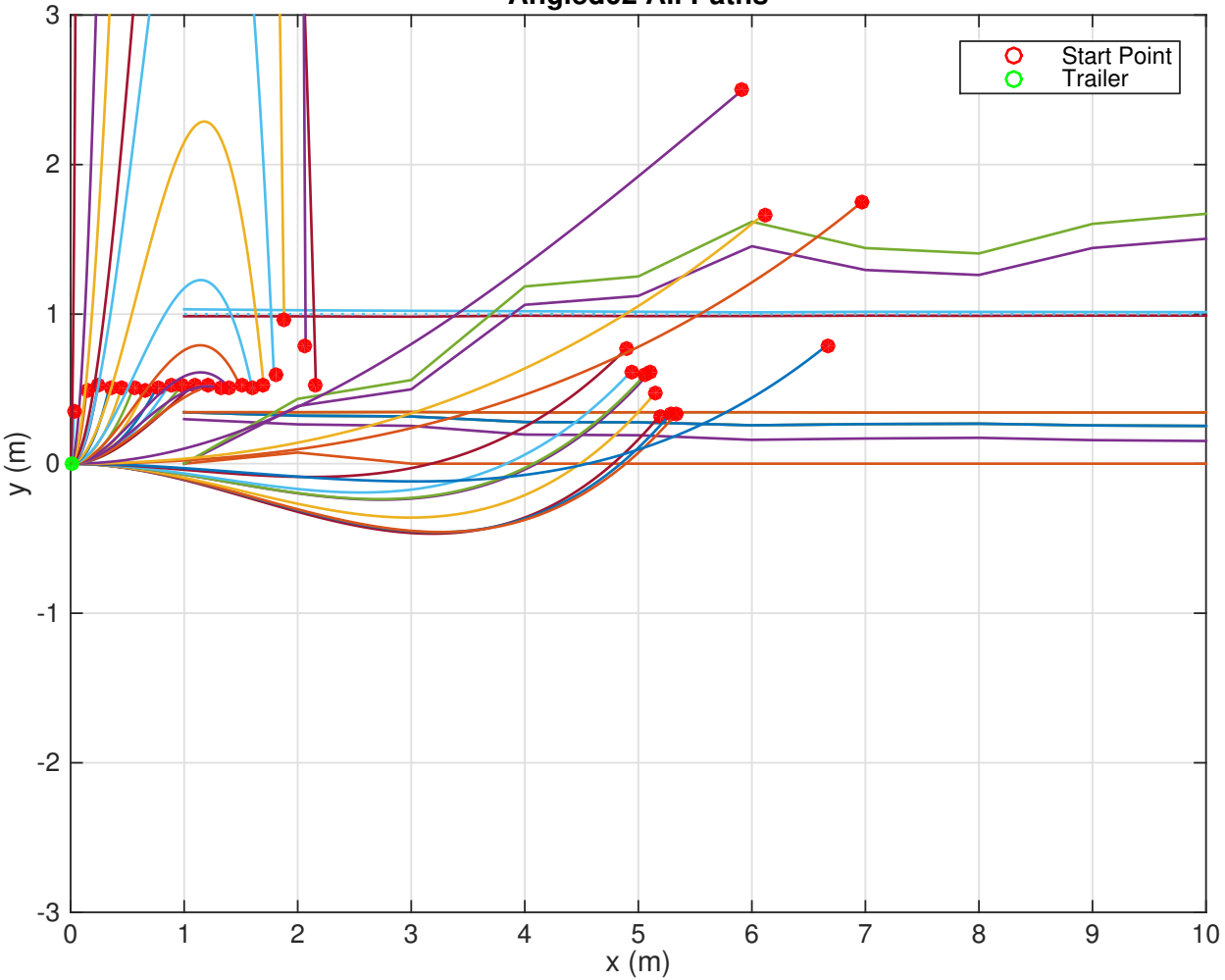
# Angled01 Camera Angles and Edge Distances



Angled01 Calculated vs. Actual Steering



## Angled02 All Paths



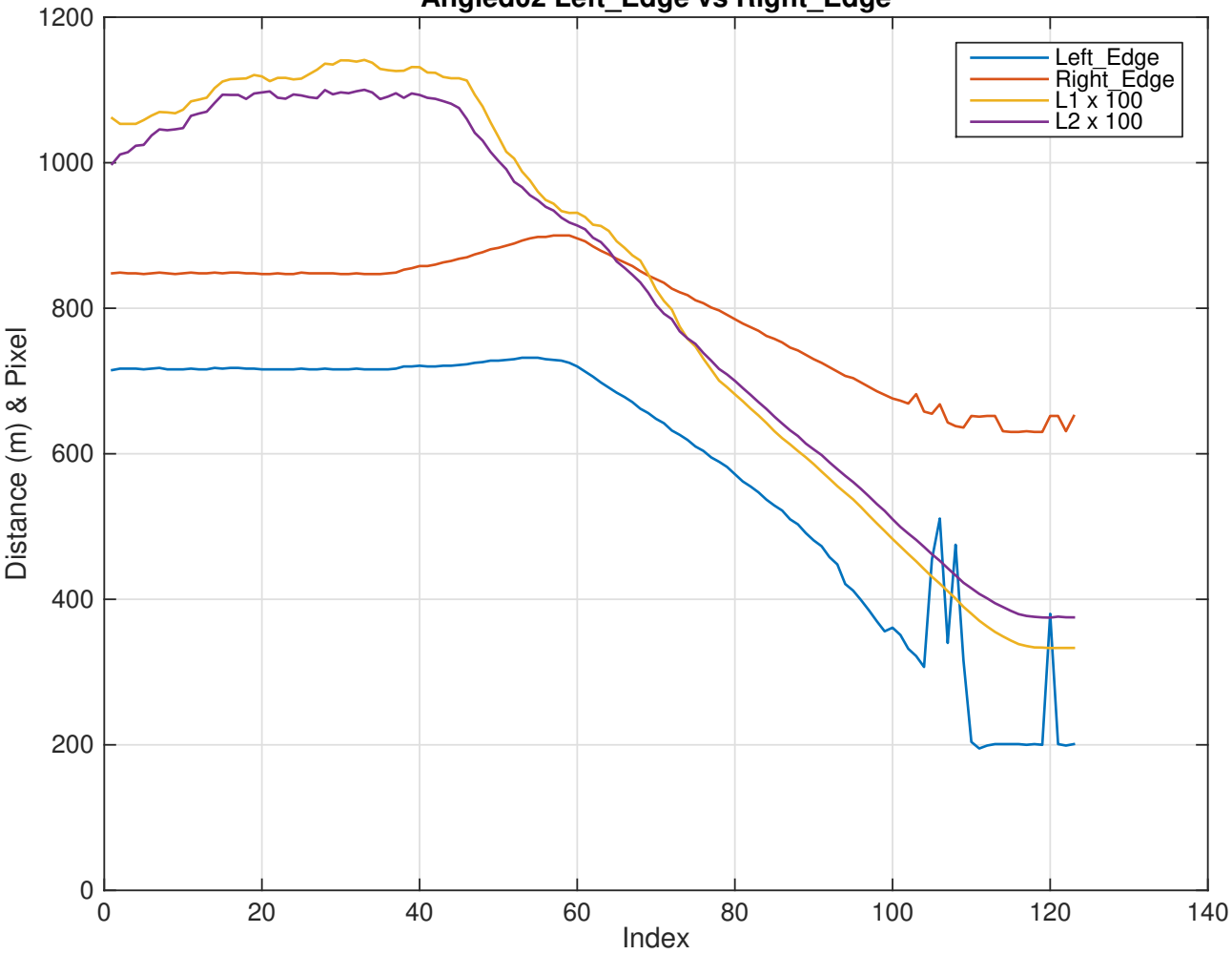
Number\_Of\_Unique\_Paths

King\_Pin\_Detected

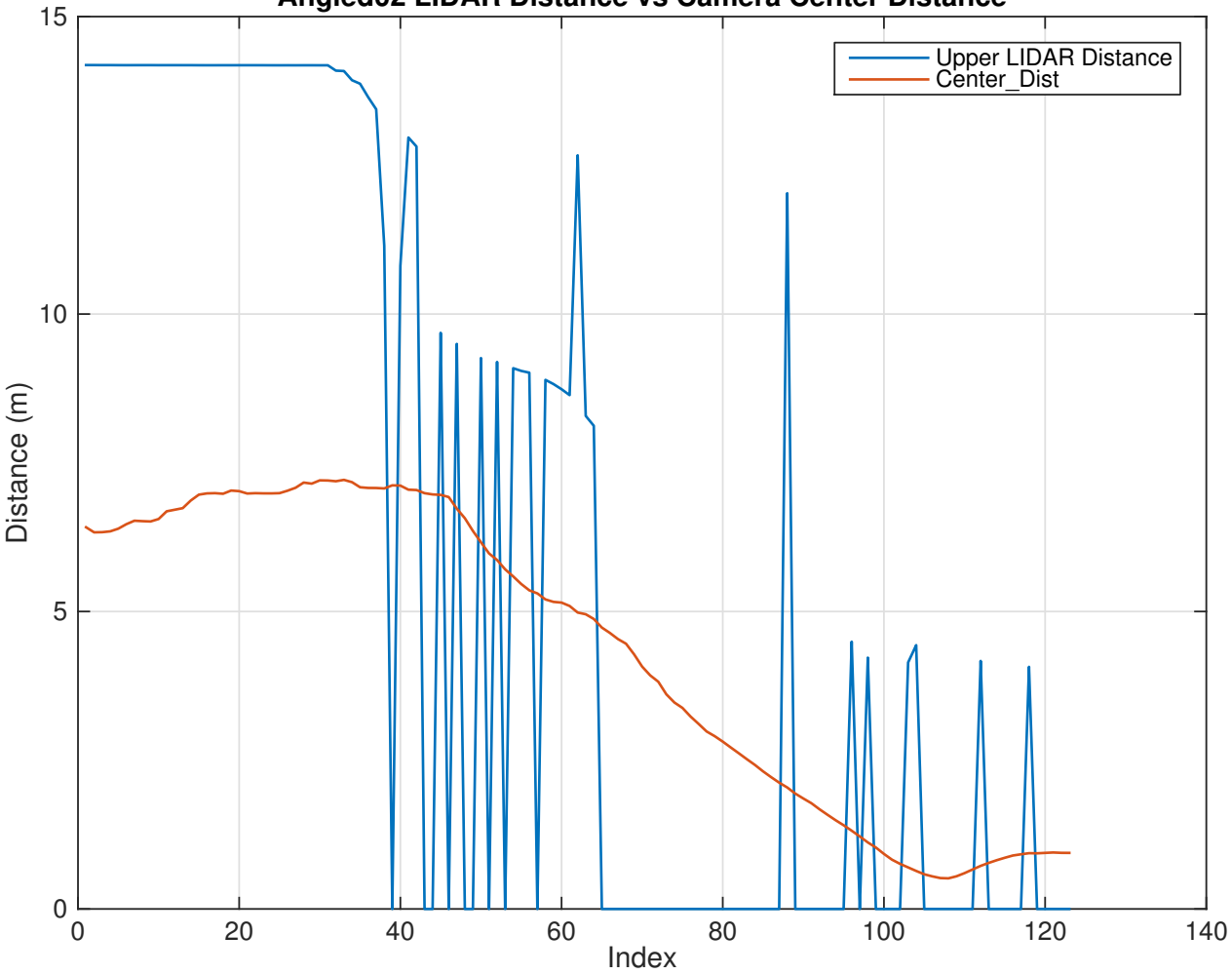
15

false

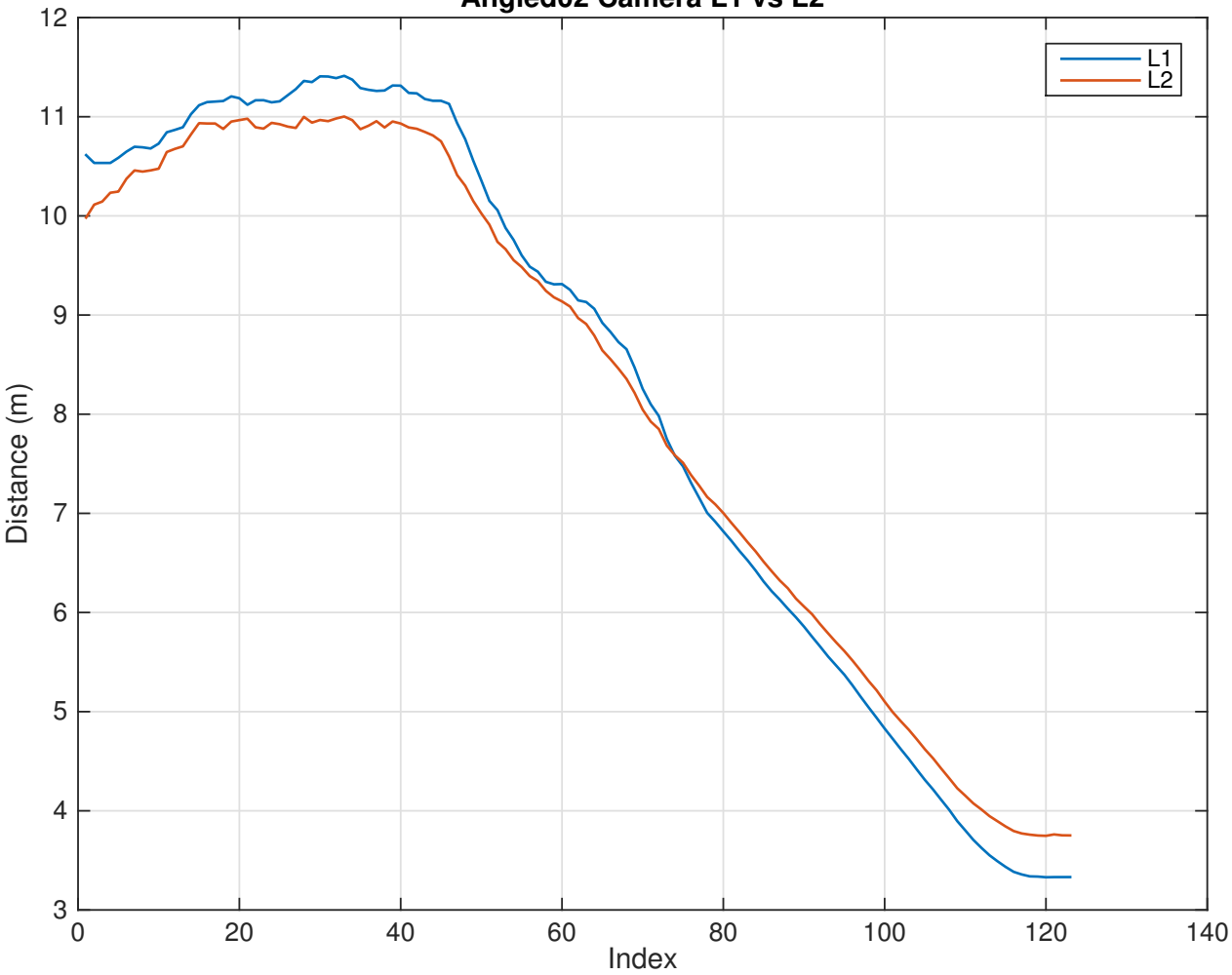
Angled02 Left\_Edge vs Right\_Edge



Angled02 LIDAR Distance vs Camera Center Distance

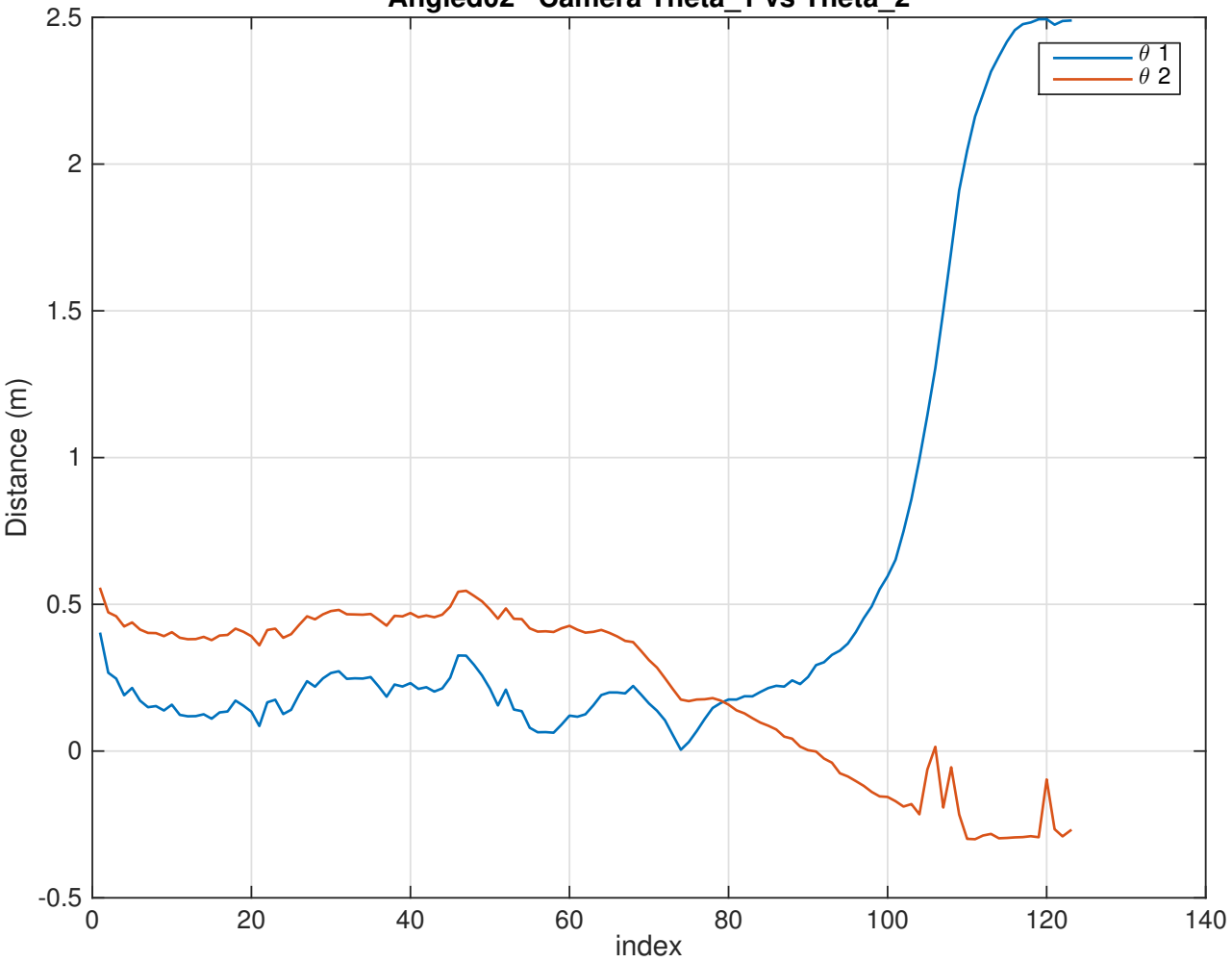


Angled02 Camera L1 vs L2

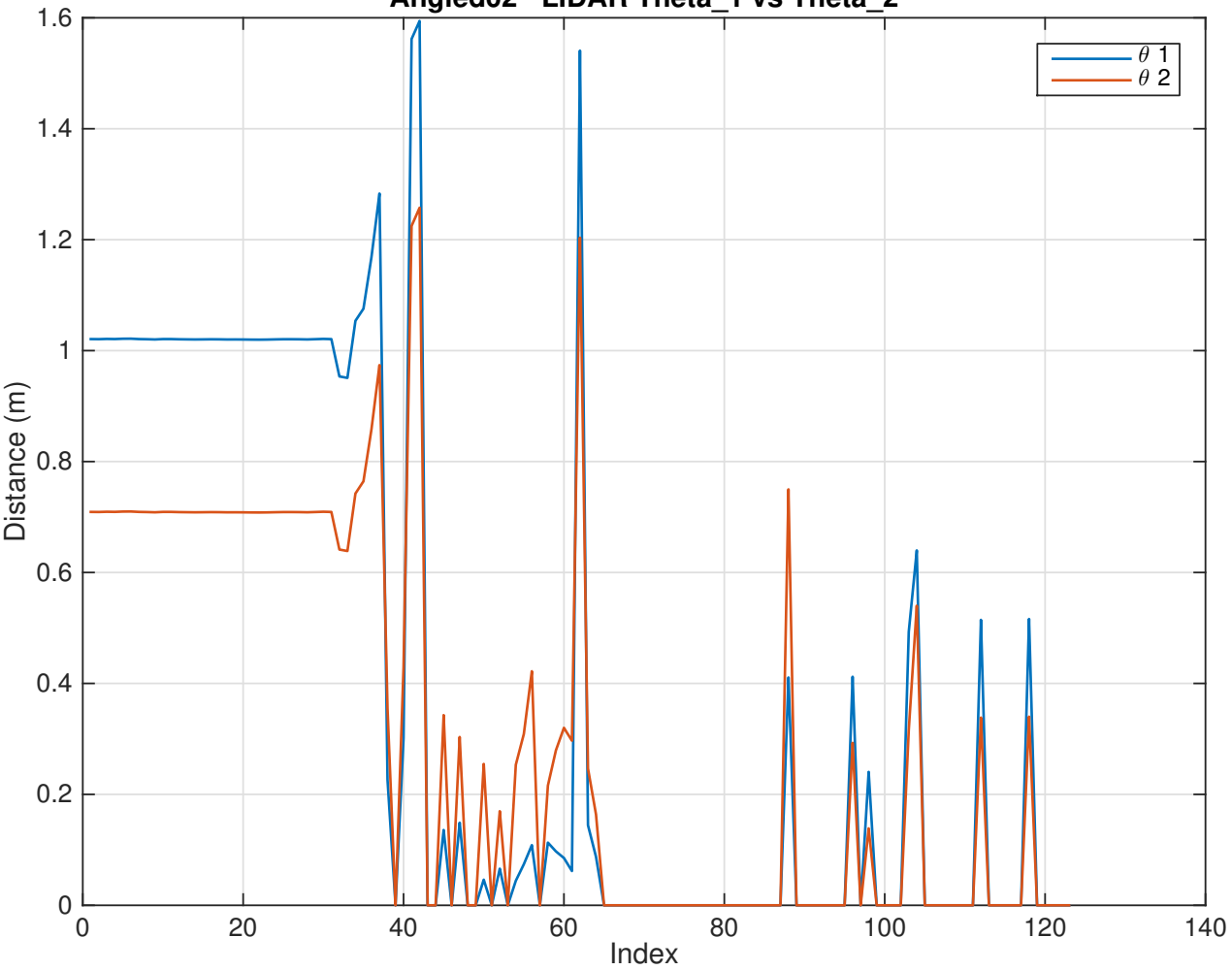




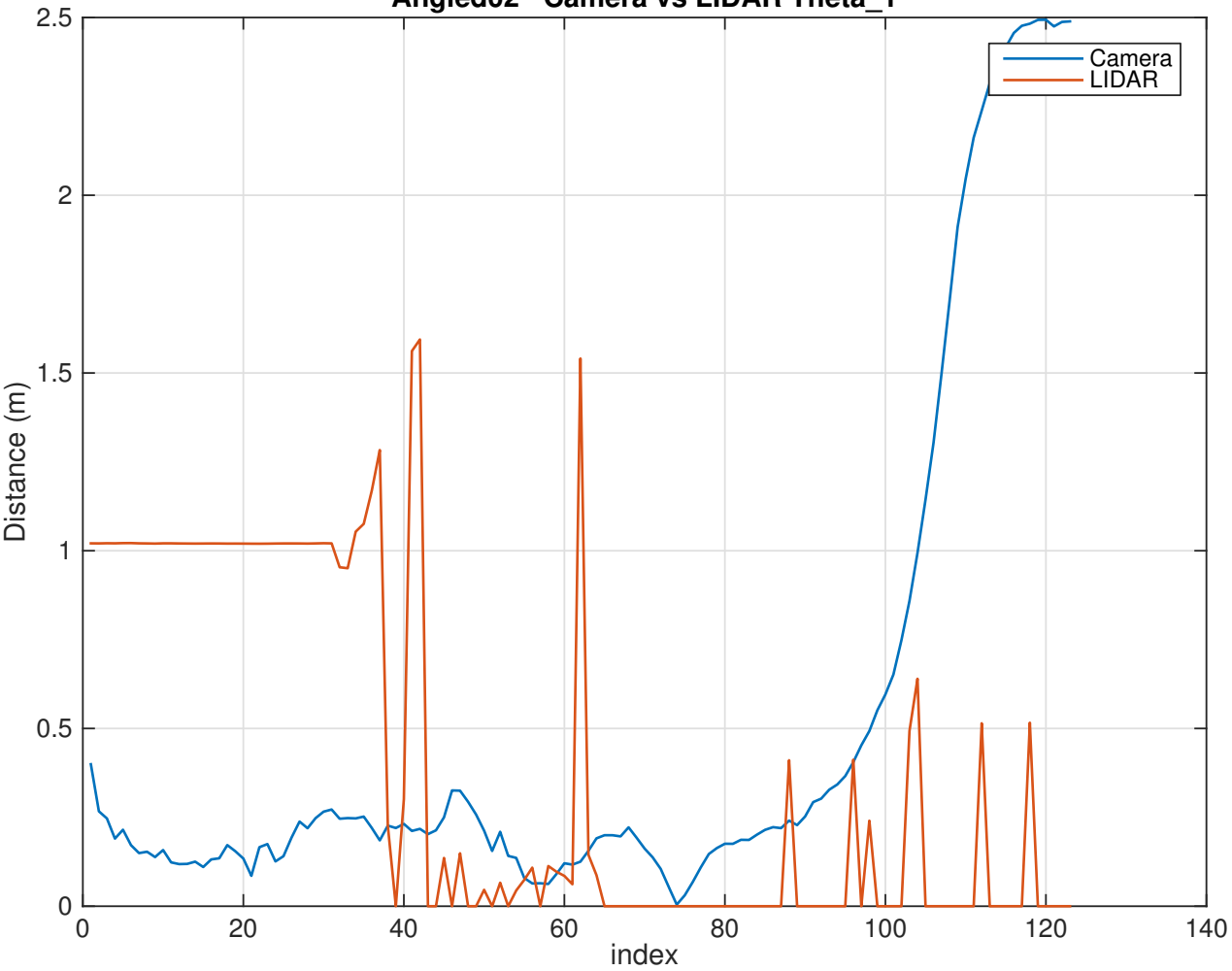
Angled02 Camera Theta\_1 vs Theta\_2



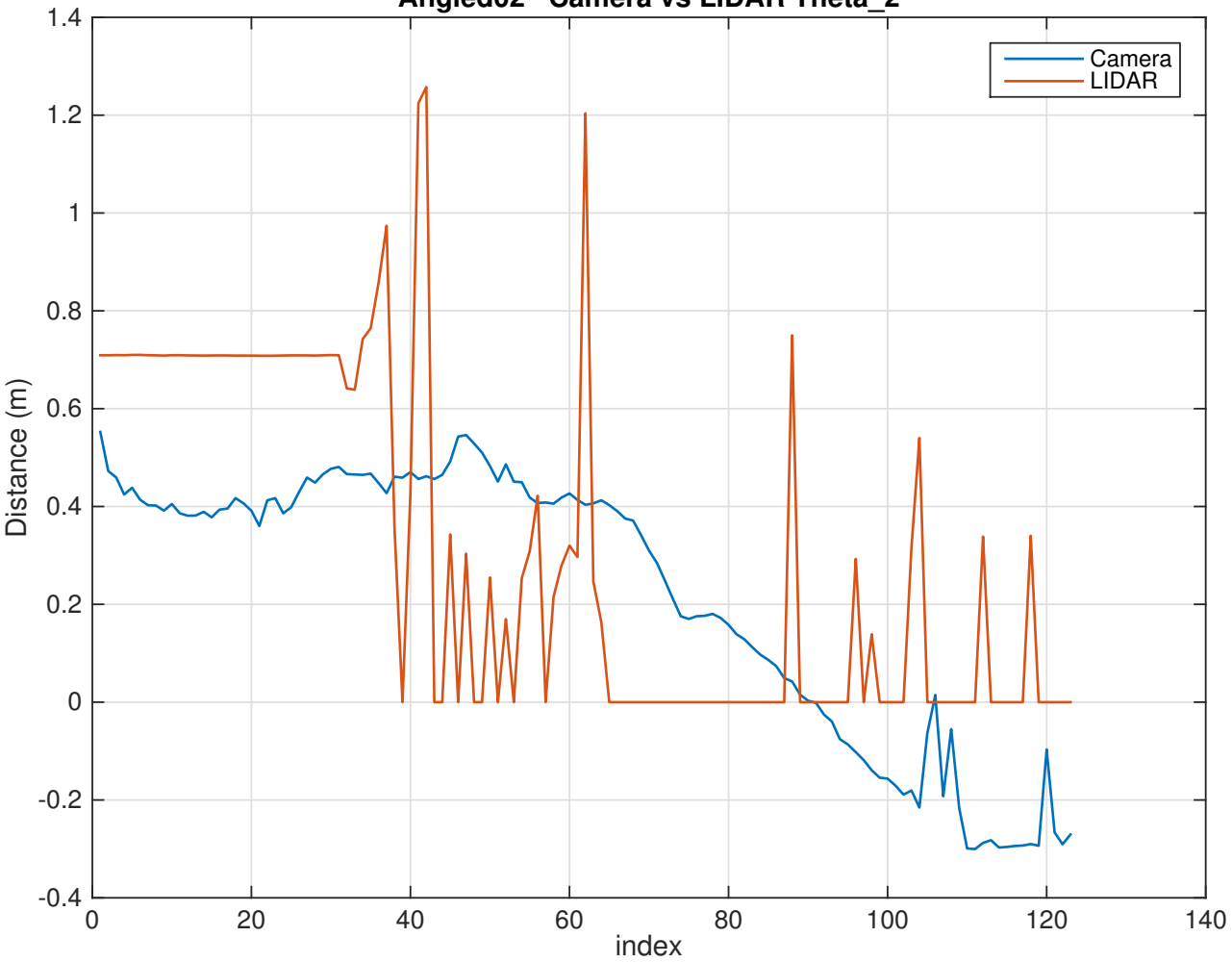
Angled02 LIDAR Theta\_1 vs Theta\_2



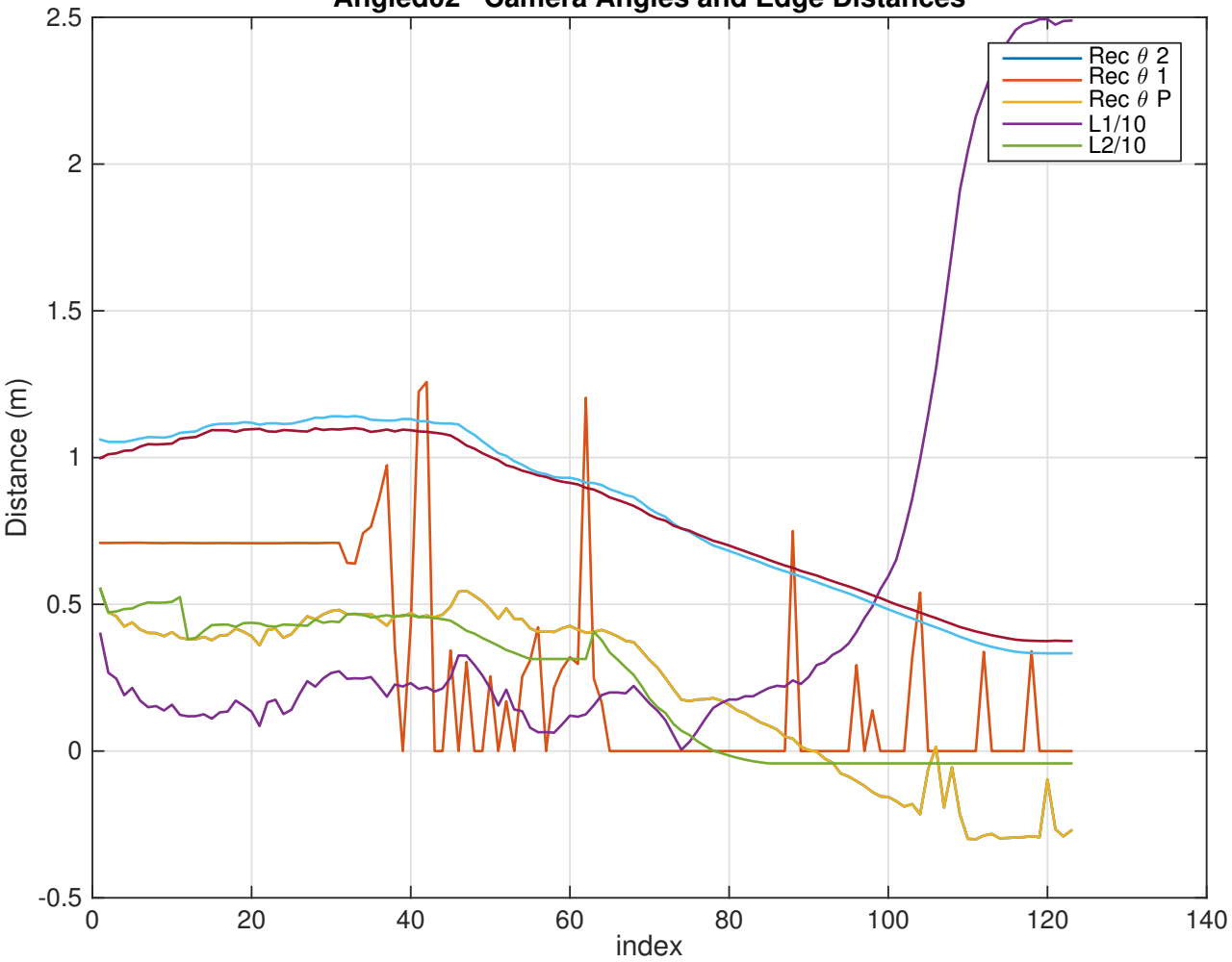
Angled02 Camera vs LIDAR Theta\_1



Angled02 Camera vs LIDAR Theta\_2



Angled02 Camera Angles and Edge Distances



# Angled02 Calculated vs. Actual Steering

