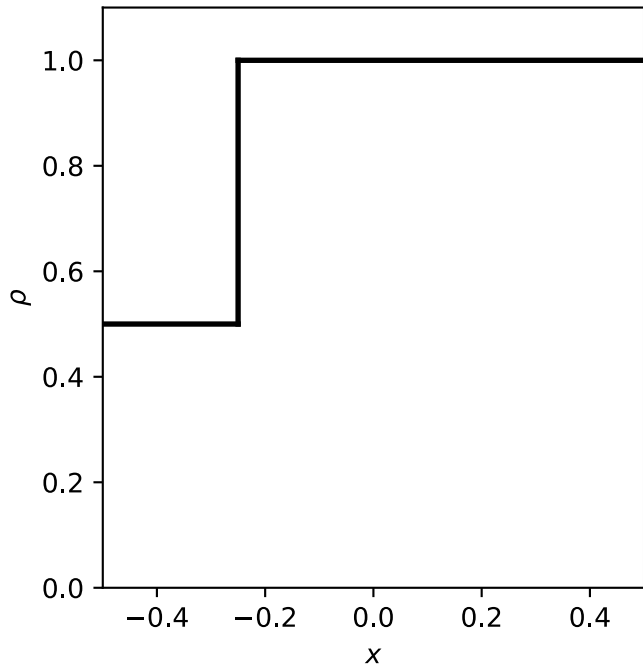


$t = 0.5$



Vehicle trajectories

