

#####parking maneuver step#####

```
def parking_maneuver():
    time.sleep(3);
    #calculate T-max and Ø-max
    maneuver.calculate_maneuverTime(vehicle);
    maneuver.calculate_max_steeringAng(vehicle);
    time.sleep(3);
    sensor_obstacle_rearCenter.listen(lambda data: control_maneuver(data));

def control_maneuver(data):
    for t in numpy.arange(0,config.T,config.sampling_period):
        if data.distance <= 1.2: #check distance to rear car
            vehicle.apply_control(carla.VehicleControl(steer=0,throttle=0));
            break;
        maneuver.parking(t,vehicle);
        time.sleep(0.05);
```