```
#.....................calculation of T (whole time of parking maneuver).................
def calculate_maneuverTime(vehicle):
        x=vehicle.get_location().x;
        y=vehicle.get_location().y;

        orientAngl=vehicle.get_transform().rotation.yaw;
        ts=0;
        cond = True;
        while cond:
          for ts in numpy.arange(0,config.T,config.sampling_period):
            s_angle = steeringAngle(ts);
            velo = velocity(ts);
            if(s_angle == 0):
               orientAngl_lastStep = orientAngl;
               orientAngl = orientAngl;
               x = x + (velo * config.sampling_period * math.cos(orientAngl));
               y = y + (velo * config.sampling_period * math.sin(orientAngl));
            else:
              orientAngl_lastStep = orientAngl;
              orientAngl = orientAngl + (((velo * config.sampling_period)/config.vehicle_length)*math.sin(s_angle));
              x =  x + ((config.vehicle_length / math.tan(s_angle)) * (math.sin(orientAngl) - math.sin(orientAngl_lastStep)));
              y =  y - ((config.vehicle_length / math.tan(s_angle)) * (math.cos(orientAngl) - math.cos(orientAngl_lastStep)));

          cond=longitudinal_condition(vehicle.get_location().x,x,vehicle.get_location().y,y,vehicle.get_transform().rotation.yaw);
          print('longitudinal cond:', cond);
          config.T += config.sampling_period;
          print('T calc values',config.T);
        config.T -= config.sampling_period;
```