* Many parts of the algorithm are being skipped because there are not enough points - added prints in a separate branch to show how far it gets and what it's skipping
* If we plot ALL of the points, we can see a plot of the general path, but turns overlap because the map only updates once (because it plots all the points at once)
* If we merge some frames and plot them, we cannot see a reasonable shape of the plot, but we do get enough separate data to update points by comparing to the previous PCL. This gives us a pose but it is not so accurate (possibly because still not enough points)
* Maybe the solution is to plot this pose on top of ALL the points plotted together - or some sort of combination like this
* The grid step also affects the pose - still need to figure out why
* How to reduce the graph size, when changing parameters sometimes I lose the plot
* The parameters I'm playing with (i.e. gridStep, maxRange, Frames etc.) need to be changed depending on the data?? - I cannot use the same parameters for 11-08-2022 Data vs 30-08-2022 Data. Matlab throws an error