UDACITY

‹ Back to Self-Driving Car Engineer

Unscented Kalman Filters

REVIEW

CODE REVIEW 11

HISTORY

▾ src/ukf.cpp 11

```
#include "ukf.h"
#include "Eigen/Dense"
#include <iostream>

#define EPS 0.001

using namespace std;
using Eigen::MatrixXd;
using Eigen::VectorXd;
using std::vector;

/**
 * Initializes Unscented Kalman filter
 * This is scaffolding, do not modify
 */
UKF::UKF() {
  // if this is false, laser measurements will be ignored (except during init)
  use_laser_ = true;

  // if this is false, radar measurements will be ignored (except during init)
  use_radar_ = true;

  // initial state vector
  x_ = VectorXd(5);

  // initial covariance matrix
    P_ = MatrixXd(5, 5);
    P_ << 1, 0, 0, 0, 0,
    0, 1, 0, 0, 0,
    0, 0, 1, 0, 0,
    0, 0, 0, 1, 0,
    0, 0, 0, 0, 1;
```

AWESOME

Initializing `P_` with an identity matrix is a good way to go!

```

 // Process noise standard deviation longitudinal acceleration in m/s^2
 std_a_ = 1.5;

 // Process noise standard deviation yaw acceleration in rad/s^2
 std_yawdd_ = 0.5;
```

AWESOME

Good choice of `std_a_` and `std_yawdd_` values.

```

 //DO NOT MODIFY measurement noise values below these are provided by the sensor manufa
 // Laser measurement noise standard deviation position1 in m
 std_laspx_ = 0.15;

 // Laser measurement noise standard deviation position2 in m
 std_laspy_ = 0.15;

 // Radar measurement noise standard deviation radius in m
 std_radr_ = 0.3;

 // Radar measurement noise standard deviation angle in rad
 std_radphi_ = 0.03;

 // Radar measurement noise standard deviation radius change in m/s
 std_radrd_ = 0.3;
 //DO NOT MODIFY measurement noise values above these are provided by the sensor manufa

 /**
 TODO:

 Complete the initialization. See ukf.h for other member properties.

 Hint: one or more values initialized above might be wildly off...
 */
 // intialize set to False. Set to true after 1st measurement
   is_initialized_ = false;

// time when the state is true, in us
   time_us_ = 0;

   // state dimension
   n_x_ = 5;

   // aumented state dimension
   n_aug_ = 7;

   ///* Sigma points dimension
   n_sig_ = 2 * n_aug_ + 1;

   // Sigma point spreading parameter
   lambda_ = 3 - n_x_;

   // Initialize weights.
   weights_ = VectorXd(n_sig_);
   weights_.fill(0.5 / (n_aug_ + lambda_));
   weights_(0) = lambda_ / (lambda_ + n_aug_);
```

AWESOME

Great to see you set the weights early on, in the constructor itself.

```

    //Predicted sigma points matrix
    Xsig_pred_ = MatrixXd(n_x_, n_sig_);

    // the current NIS for radar
    NIS_radar_ = 0.0;

    // the current NIS for laser
    NIS_lidar_ = 0.0;

    // Initlialize measure noise covariance
    R_radar_ =  MatrixXd(3,3);
    R_lidar_ = MatrixXd(2,2);
    R_radar_ << std_radr_*std_radr_,0,0,
                0,std_radphi_*std_radphi_,0,
                0,0, std_radrd_*std_radrd_;
    R_lidar_ << std_laspx_*std_laspx_,0,
                0, std_laspy_*std_laspy_;
```

SUGGESTION

Great to see you prepared these matrices in the constructor itself.

```


}

UKF::~UKF() {}

/**
 * @param {MeasurementPackage} meas_package The latest measurement data of
 * either radar or laser.
 */
void UKF::ProcessMeasurement(MeasurementPackage meas_package) {
    /**
     TODO:

     Complete this function! Make sure you switch between lidar and radar
     measurements.
     */
    if ( !is_initialized_) {
        if (meas_package.sensor_type_ == MeasurementPackage::RADAR) {
            double rho = meas_package.raw_measurements_[0]; // range
            double phi = meas_package.raw_measurements_[1]; // bearing
            double rho_dot = meas_package.raw_measurements_[2]; // velocity of rho
            double x = rho * cos(phi);
            double y = rho * sin(phi);
            double vx = rho_dot * cos(phi);
            double vy = rho_dot * sin(phi);
            double v = sqrt(vx * vx + vy * vy);
```

SUGGESTION

Here `v` evaluates to `rho_dot` itself due to the trigonometry identity `sin^2(theta) + cos^(theta) = 1`

```
            x_ << x, y, v, 0, 0;
```

```
        } else {
            x_ << meas_package.raw_measurements_[0], meas_package.raw_measurements_[1],
        }

        // Saving first timestamp in seconds
        time_us_ = meas_package.timestamp_ ;
        // done initializing, no need to predict or update
        is_initialized_ = true;
        return;
    }

    // Calculate dt
    double dt = (meas_package.timestamp_ - time_us_) / 1000000.0;
    time_us_ = meas_package.timestamp_;
    // Prediction step
    //cout<<"DEBUG: Prediction Starts" << endl;

    Prediction(dt);
    //cout<<"DEBUG: Prediction Ends" << endl;


    if (meas_package.sensor_type_ == MeasurementPackage::RADAR && use_radar_) {
        UpdateRadar(meas_package);
    }
    if (meas_package.sensor_type_ == MeasurementPackage::LASER && use_laser_) {
        UpdateLidar(meas_package);
    }
}
/**
 * Predicts sigma points, the state, and the state covariance matrix.
 * @param {double} delta_t the change in time (in seconds) between the last
 * measurement and this one.
 */
void UKF::Prediction(double delta_t) {
    /**
     TODO:

     Complete this function! Estimate the object's location. Modify the state
     vector, x_. Predict sigma points, the state, and the state covariance matrix.
     */

    // 1. Generate sigma points.
    //create augmented mean vector
    VectorXd x_aug = VectorXd(n_aug_);
    x_aug.head(5) = x_;
    x_aug(5) = 0;
    x_aug(6) = 0;

    //create augmented state covariance
    MatrixXd P_aug = MatrixXd(n_aug_, n_aug_);
    P_aug.fill(0.0);
    P_aug.topLeftCorner(n_x_,n_x_) = P_;
    P_aug(5,5) = std_a_*std_a_;
    P_aug(6,6) = std_yawdd_*std_yawdd_;
```

SUGGESTION

You can prepare this Q matrix in the constructor itself because it does not change over iterations.

```

    // Creating sigma points.
    MatrixXd Xsig_aug = GenerateSigmaPoints(x_aug, P_aug, lambda_, n_sig_);

    // 2. Predict Sigma Points.
```

```
    Xsig_pred_ = PredictSigmaPoints(Xsig_aug, delta_t, n_x_, n_sig_, std_a_, std_yawdd_)

    // 3. Predict Mean and Covariance
    //predicted state mean
    x_ = Xsig_pred_ * weights_;

    cout << " DEBUG: Predict x_= " << x_ << endl;

    //predicted state covariance matrix
    P_.fill(0.0);
    for (int i = 0; i < n_sig_; i++) {  //iterate over sigma points

        // state difference
        VectorXd x_diff = Xsig_pred_.col(i) - x_;
        //angle normalization
        x_diff = NormalizeAngle(x_diff, 3);

        P_ = P_ + weights_(i) * x_diff * x_diff.transpose() ;
    }

}
```

AWESOME

I liked how you divided the `Prediction` part into three subparts with two sub-functions. This makes it easier to go thr also easy to maintain.

```


/**
 * Updates the state and the state covariance matrix using a laser measurement.
 * @param {MeasurementPackage} meas_package
 */
void UKF::UpdateLidar(MeasurementPackage meas_package) {
```

SUGGESTION

You can update lidar using the linear method as you did in the EKF project. Because lidar measurement model is a line save computational burden.

```
  /**
  TODO:

  Complete this function! Use lidar data to update the belief about the object's
  position. Modify the state vector, x_, and covariance, P_.

  You'll also need to calculate the lidar NIS.
  */

    int n_z = 2;

     //Step 1: Predict measurement mean and covariance
    //create example matrix with sigma points in measurement space

    MatrixXd Zsig = Xsig_pred_.block(0,0,n_z,n_sig_);

    //Create example vector for mean predicted measurement
    VectorXd z_pred = VectorXd(n_z);
    z_pred.fill(0.0);
    for (int i=0; i < n_sig_; i++) {
        z_pred = z_pred + weights_(i) * Zsig.col(i);
```

```
    }

    //Create example vector for covariance predicted measurement
    MatrixXd S = MatrixXd(n_z,n_z);
    S.fill(0.0);
    for (int i = 0; i < n_sig_; i++) {
        //residual
        VectorXd z_diff = Zsig.col(i) - z_pred;
        S = S + weights_(i) * z_diff * z_diff.transpose();
    }

    //add measurement noise covariance matrix
    S = S + R_lidar_;

     //Step 2: Update State mean and Covariance

    // Incoming lidar measurement
    VectorXd z = meas_package.raw_measurements_;

    //Cross-correlation between sigma opints in state space and measurement space
    MatrixXd Tc = MatrixXd(n_x_,n_z);
    Tc.fill(0.0);
    for (int i = 0; i < n_sig_; i++) {  //2n+1 simga points

        //residual
        VectorXd z_diff = Zsig.col(i) - z_pred;

        // state difference
        VectorXd x_diff = Xsig_pred_.col(i) - x_;

        Tc = Tc + weights_(i) * x_diff * z_diff.transpose();
    }

    //Kalman gain K;
    MatrixXd K = Tc * S.inverse();

    //residual
    VectorXd z_diff = z - z_pred;

    //update state mean and covariance
    x_ = x_ + K * z_diff;
    P_ = P_ - K*S*K.transpose();
    cout << "DEBUG: UpdateLidar x_ = " << x_ <<endl;

    //NIS Lidar Update
    NIS_lidar_ = z_diff.transpose() * S.inverse() * z_diff;
}

/**
 * Updates the state and the state covariance matrix using a radar measurement.
 * @param {MeasurementPackage} meas_package
 */
void UKF::UpdateRadar(MeasurementPackage meas_package) {
  /**
  TODO:

  Complete this function! Use radar data to update the belief about the object's
  position. Modify the state vector, x_, and covariance, P_.

  You'll also need to calculate the radar NIS.
  */

    //Radar dimension
    int n_z = 3;

// Step 1: Predict measurement mean and covariance
```

```

    // create example matrix with sigma points in measurement space
    MatrixXd Zsig = MatrixXd(n_z,n_sig_);

    //transform sigma points into measurement space

    for (int i = 0; i < n_sig_ ; i++) {  //2n+1 simga points

        // extract values for better readibility
        double p_x = Xsig_pred_(0,i);
        double p_y = Xsig_pred_(1,i);
        double v  = Xsig_pred_(2,i);
        double yaw = Xsig_pred_(3,i);

        double v1 = cos(yaw)*v;
        double v2 = sin(yaw)*v;

        // measurement model
        Zsig(0,i) = sqrt(p_x*p_x + p_y*p_y);                        //r
        Zsig(1,i) = atan2(p_y,p_x);                                 //phi
        Zsig(2,i) = (p_x*v1 + p_y*v2 ) / sqrt(p_x*p_x + p_y*p_y);   //r_dot
    }

    //Create example vector for mean predicted measurement
    VectorXd z_pred = VectorXd(n_z);
    z_pred.fill(0.0);
    for (int i=0; i < n_sig_; i++) {
        z_pred = z_pred + weights_(i) * Zsig.col(i);
    }

    //Create example vector for covariance predicted measurement
    MatrixXd S = MatrixXd(n_z,n_z);
    S.fill(0.0);
    for (int i = 0; i < n_sig_; i++) {  //2n+1 simga points
        //residual
        VectorXd z_diff = Zsig.col(i) - z_pred;

        //angle normalization
        z_diff = NormalizeAngle(z_diff, 1);

        S = S + weights_(i) * z_diff * z_diff.transpose();
    }

    //add measurement noise covariance matrix
    S = S + R_radar_;

// Step 2: Update State mean and Covariance

    VectorXd z = meas_package.raw_measurements_;

    //Cross-correlation between sigma opints in state space and measurement space
    MatrixXd Tc = MatrixXd(n_x_,n_z);
    Tc.fill(0.0);

    for (int i = 0; i < n_sig_; i++) {  //2n+1 simga points

        //residual
        VectorXd z_diff = Zsig.col(i) - z_pred;

        //normalize angle
        z_diff = NormalizeAngle(z_diff, 1);

        // state difference
        VectorXd x_diff = Xsig_pred_.col(i) - x_;
        //normalize angle
        NormalizeAngle(x_diff, 3);
```

```
        Tc = Tc + weights_(i) * x_diff * z_diff.transpose();
    }

    //Kalman gain K;
    MatrixXd K = Tc * S.inverse();

    //residual
    VectorXd z_diff = z - z_pred;
    //angle normalization
    NormalizeAngle(z_diff, 1);

    //update state mean and covariance
    x_ = x_ + K * z_diff;
    P_ = P_ - K*S*K.transpose();
    cout <<"DEBUG: Update Radar: x_ = " << x_ << endl;

    //NIS Radar Update
    NIS_radar_ = z_diff.transpose() * S.inverse() * z_diff;


   }

/*******************************************************************************
 *  Generate Sigma Points
 ******************************************************************************/
MatrixXd UKF::GenerateSigmaPoints(VectorXd x, MatrixXd P, double lambda, int n_sig)
{
    int n = x.size();
    //create sigma point matrix
    MatrixXd Xsig = MatrixXd( n, n_sig );

    //calculate square root of P
    MatrixXd A = P.llt().matrixL();

    Xsig.col(0) = x;

    double lambda_plus_n_x_sqrt = sqrt(lambda + n);
    for (int i = 0; i < n; i++){
        Xsig.col( i + 1 ) = x + lambda_plus_n_x_sqrt * A.col(i);
        Xsig.col( i + 1 + n ) = x - lambda_plus_n_x_sqrt * A.col(i);
    }
    return Xsig;
}

/*******************************************************************************
 *  Predict Sigma Points with process noise
 ******************************************************************************/
MatrixXd UKF::PredictSigmaPoints(MatrixXd Xsig, double delta_t, int n_x, int n_sig, doub
{
    MatrixXd Xsig_pred = MatrixXd(n_x,n_sig);

    for (int i = 0; i< n_sig; i++)
    {
        double p_x = Xsig(0,i);
        double p_y = Xsig(1,i);
        double v = Xsig(2,i);
        double yaw = Xsig(3,i);
        double yawd = Xsig(4,i);
        double nu_a = Xsig(5,i);
        double nu_yawdd = Xsig(6,i);
```

SUGGESTION

It would be good to declare variables that will not or should not change in the current scope as `const` throughout you help to optimize the code while compilation.

```

        //predicted state values
        double px_p, py_p;

        //avoid division by zero
        if (fabs(yawd) > EPS) {
            px_p = p_x + v/yawd * ( sin (yaw + yawd*delta_t) - sin(yaw));
            py_p = p_y + v/yawd * ( cos(yaw) - cos(yaw+yawd*delta_t) );
        }
        else {
            px_p = p_x + v*delta_t*cos(yaw);
            py_p = p_y + v*delta_t*sin(yaw);
        }

        double v_p = v;
        double yaw_p = yaw + yawd*delta_t;
        double yawd_p = yawd;

        //add noise
        px_p = px_p + 0.5*nu_a*delta_t*delta_t * cos(yaw);
        py_p = py_p + 0.5*nu_a*delta_t*delta_t * sin(yaw);
        v_p = v_p + nu_a*delta_t;

        yaw_p = yaw_p + 0.5*nu_yawdd*delta_t*delta_t;
        yawd_p = yawd_p + nu_yawdd*delta_t;

        //write predicted sigma points into Sigma Matrix
        Xsig_pred(0,i) = px_p;
        Xsig_pred(1,i) = py_p;
        Xsig_pred(2,i) = v_p;
        Xsig_pred(3,i) = yaw_p;
        Xsig_pred(4,i) = yawd_p;
    }

    return Xsig_pred;
}

VectorXd UKF::NormalizeAngle(VectorXd vector, int angleIdx)
{
    while (vector(angleIdx) > M_PI) vector(angleIdx)-= 2*M_PI;
    while (vector(angleIdx) < -M_PI) vector(angleIdx)+= 2*M_PI;
    return vector;
```

AWESOME

Great to see that you made a function for normalizing the angles.

```
}
```

AWESOME

Overall I liked how your comments are well-structured throughout the code. This makes it easier to go through the coc

▸ src/ukf.h

- src/tools.h
- src/tools.cpp
- src/measurement_package.h
- src/main.cpp
- src/Eigen/src/plugins/MatrixCwiseUnaryOps.h
- src/Eigen/src/plugins/MatrixCwiseBinaryOps.h
- src/Eigen/src/plugins/CommonCwiseUnaryOps.h
- src/Eigen/src/plugins/CommonCwiseBinaryOps.h
- src/Eigen/src/Geometry/Homogeneous.h
- src/Eigen/src/Geometry/EulerAngles.h
- src/Eigen/src/Geometry/CMakeLists.txt
- src/Eigen/src/Geometry/AngleAxis.h
- src/Eigen/src/Geometry/AlignedBox.h
- src/Eigen/src/Eigenvalues/Tridiagonalization.h
- src/Eigen/src/Eigenvalues/RealSchur_MKL.h
- src/Eigen/src/Eigenvalues/RealSchur.h
- src/Eigen/src/Eigenvalues/RealQZ.h
- src/Eigen/src/Eigenvalues/HessenbergDecomposition.h
- src/Eigen/src/Eigenvalues/ComplexSchur_MKL.h
- src/Eigen/src/Eigenvalues/ComplexSchur.h
- src/Eigen/src/Eigenvalues/CMakeLists.txt
- src/Eigen/src/Eigen2Support/VectorBlock.h

- src/Eigen/src/Eigen2Support/TriangularSolver.h
- src/Eigen/src/Eigen2Support/SVD.h
- src/Eigen/src/Eigen2Support/QR.h
- src/Eigen/src/Eigen2Support/Minor.h
- src/Eigen/src/Eigen2Support/Meta.h
- src/Eigen/src/Eigen2Support/Memory.h
- src/Eigen/src/Eigen2Support/MathFunctions.h
- src/Eigen/src/Eigen2Support/Macros.h
- src/Eigen/src/Eigen2Support/LeastSquares.h
- src/Eigen/src/Eigen2Support/Lazy.h
- src/Eigen/src/Eigen2Support/LU.h
- src/Eigen/src/Eigen2Support/Geometry/Translation.h
- src/Eigen/src/Eigen2Support/Geometry/Transform.h
- src/Eigen/src/Eigen2Support/Geometry/Scaling.h
- src/Eigen/src/Eigen2Support/Geometry/RotationBase.h
- src/Eigen/src/Eigen2Support/Geometry/Rotation2D.h
- src/Eigen/src/Eigen2Support/Geometry/Quaternion.h
- src/Eigen/src/Eigen2Support/Geometry/ParametrizedLine.h
- src/Eigen/src/Eigen2Support/Geometry/Hyperplane.h
- src/Eigen/src/Eigen2Support/Geometry/CMakeLists.txt
- src/Eigen/src/Eigen2Support/Geometry/AngleAxis.h
- src/Eigen/src/Eigen2Support/Geometry/All.h

- src/Eigen/src/Eigen2Support/Geometry/AlignedBox.h
- src/Eigen/src/Eigen2Support/CwiseOperators.h
- src/Eigen/src/Eigen2Support/Cwise.h
- src/Eigen/src/Eigen2Support/CMakeLists.txt
- src/Eigen/src/Eigen2Support/Block.h
- src/Eigen/src/Core/util/XprHelper.h
- src/Eigen/src/Core/util/StaticAssert.h
- src/Eigen/src/Core/util/ReenableStupidWarnings.h
- src/Eigen/src/Core/util/NonMPL2.h
- src/Eigen/src/Core/util/Meta.h
- src/Eigen/src/Core/util/Memory.h
- src/Eigen/src/Core/util/Macros.h
- src/Eigen/src/Core/util/MKL_support.h
- src/Eigen/src/Core/util/ForwardDeclarations.h
- src/Eigen/src/Core/util/DisableStupidWarnings.h
- src/Eigen/src/Core/util/Constants.h
- src/Eigen/src/Core/util/CMakeLists.txt
- src/Eigen/src/Core/util/BlasUtil.h
- src/Eigen/src/Core/products/TriangularSolverVector.h
- src/Eigen/src/Core/products/TriangularSolverMatrix_MKL.h
- src/Eigen/src/Core/products/TriangularSolverMatrix.h
- src/Eigen/src/Core/products/TriangularMatrixVector_MKL.h

- src/Eigen/src/Core/products/TriangularMatrixVector.h
- src/Eigen/src/Core/products/TriangularMatrixMatrix_MKL.h
- src/Eigen/src/Core/products/TriangularMatrixMatrix.h
- src/Eigen/src/Core/products/SelfadjointRank2Update.h
- src/Eigen/src/Core/products/SelfadjointProduct.h
- src/Eigen/src/Core/products/SelfadjointMatrixVector_MKL.h
- src/Eigen/src/Core/products/SelfadjointMatrixVector.h
- src/Eigen/src/Core/products/SelfadjointMatrixMatrix_MKL.h
- src/Eigen/src/Core/products/SelfadjointMatrixMatrix.h
- src/Eigen/src/Core/products/Parallelizer.h
- src/Eigen/src/Core/products/GeneralMatrixVector_MKL.h
- src/Eigen/src/Core/products/GeneralMatrixVector.h
- src/Eigen/src/Core/products/GeneralMatrixMatrix_MKL.h
- src/Eigen/src/Core/products/GeneralMatrixMatrixTriangular_MKL.h
- src/Eigen/src/Core/products/GeneralMatrixMatrixTriangular.h
- src/Eigen/src/Core/products/GeneralMatrixMatrix.h
- src/Eigen/src/Core/products/GeneralBlockPanelKernel.h
- src/Eigen/src/Core/products/CoeffBasedProduct.h
- src/Eigen/src/Core/products/CMakeLists.txt
- src/Eigen/src/Core/arch/SSE/PacketMath.h
- src/Eigen/src/Core/arch/SSE/MathFunctions.h
- src/Eigen/src/Core/arch/SSE/Complex.h

- src/Eigen/src/Core/arch/SSE/CMakeLists.txt
- src/Eigen/src/Core/arch/NEON/PacketMath.h
- src/Eigen/src/Core/arch/NEON/Complex.h
- src/Eigen/src/Core/arch/NEON/CMakeLists.txt
- src/Eigen/src/Core/arch/Default/Settings.h
- src/Eigen/src/Core/arch/Default/CMakeLists.txt
- src/Eigen/src/Core/arch/CMakeLists.txt
- src/Eigen/src/Core/arch/AltiVec/PacketMath.h
- src/Eigen/src/Core/arch/AltiVec/Complex.h
- src/Eigen/src/Core/arch/AltiVec/CMakeLists.txt
- src/Eigen/src/Core/Visitor.h
- src/Eigen/src/Core/VectorwiseOp.h
- src/Eigen/src/Core/VectorBlock.h
- src/Eigen/src/Core/TriangularMatrix.h
- src/Eigen/src/Core/Transpositions.h
- src/Eigen/src/Core/Transpose.h
- src/Eigen/src/Core/Swap.h
- src/Eigen/src/Core/Stride.h
- src/Eigen/src/Core/StableNorm.h
- src/Eigen/src/Core/SolveTriangular.h
- src/Eigen/src/Core/SelfCwiseBinaryOp.h
- src/Eigen/src/Core/SelfAdjointView.h

- src/Eigen/src/Core/Select.h
- src/Eigen/src/Core/Reverse.h
- src/Eigen/src/Core/ReturnByValue.h
- src/Eigen/src/Core/Replicate.h
- src/Eigen/src/Core/Ref.h
- src/Eigen/src/Core/Redux.h
- src/Eigen/src/Core/Random.h
- src/Eigen/src/Core/ProductBase.h
- src/Eigen/src/Core/PlainObjectBase.h
- src/Eigen/src/Core/PermutationMatrix.h
- src/Eigen/src/Core/NumTraits.h
- src/Eigen/src/Core/NoAlias.h
- src/Eigen/src/Core/NestByValue.h
- src/Eigen/src/Core/MatrixBase.h
- src/Eigen/src/Core/Matrix.h
- src/Eigen/src/Core/MathFunctions.h
- src/Eigen/src/Core/MapBase.h
- src/Eigen/src/Core/Map.h
- src/Eigen/src/Core/IO.h
- src/Eigen/src/Core/GlobalFunctions.h
- src/Eigen/src/Core/GenericPacketMath.h
- src/Eigen/src/Core/GeneralProduct.h

- src/Eigen/src/Core/Fuzzy.h
- src/Eigen/src/Core/Functors.h
- src/Eigen/src/Core/ForceAlignedAccess.h
- src/Eigen/src/Core/Flagged.h
- src/Eigen/src/Core/Dot.h
- src/Eigen/src/Core/DiagonalProduct.h
- src/Eigen/src/Core/DiagonalMatrix.h
- src/Eigen/src/Core/Diagonal.h
- src/Eigen/src/Core/DenseStorage.h
- src/Eigen/src/Core/DenseCoeffsBase.h
- src/Eigen/src/Core/DenseBase.h
- src/Eigen/src/Core/CwiseUnaryView.h
- src/Eigen/src/Core/CwiseUnaryOp.h
- src/Eigen/src/Core/CwiseNullaryOp.h
- src/Eigen/src/Core/CwiseBinaryOp.h
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- cmakepatch.txt

- README.md

- LICENSE

- CMakeLists.txt

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