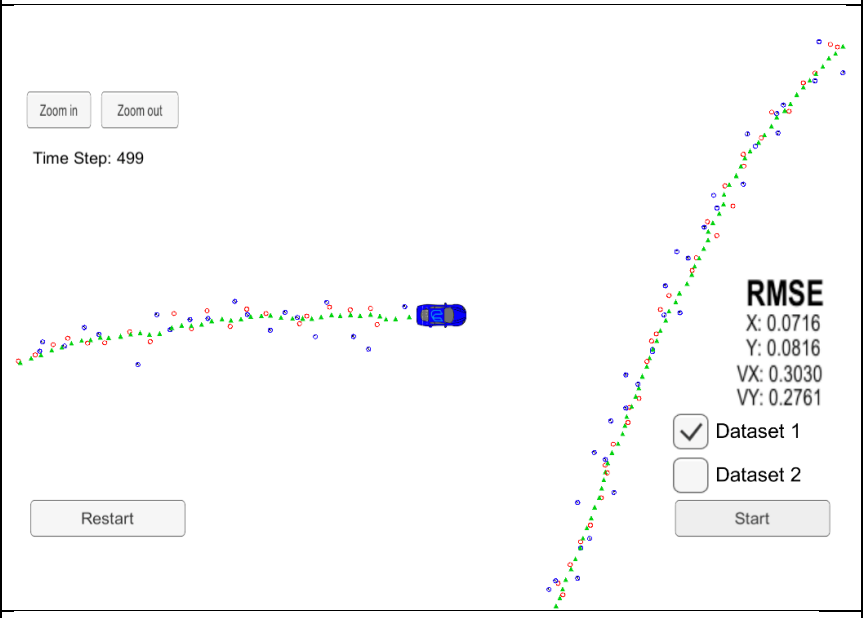
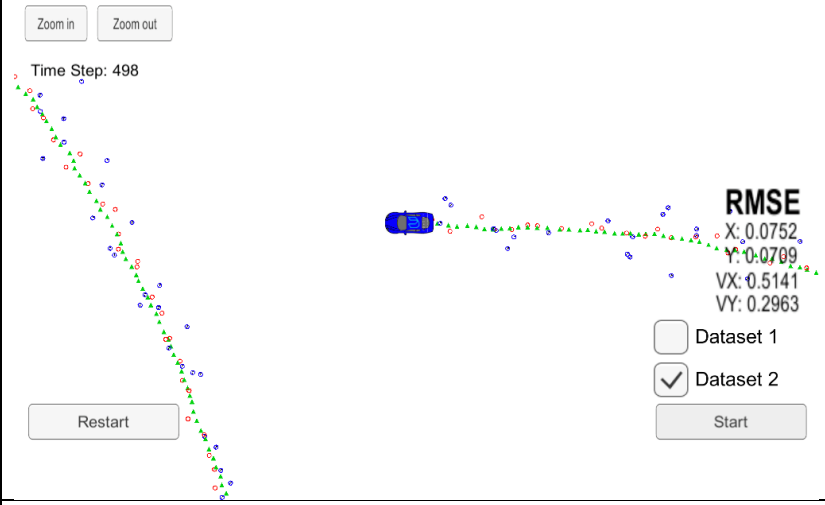
Accuracy	
For the older version of the project, your algorithm will be run against "sample-laser-radar-measurement-data-1.txt". We'll collect the positions that your algorithm outputs and compare them to ground truth data. Your px, py, vx, and vy RMSE should be less than or equal to the values [0.09, 0.09, 0.65, 0.65].	
For the older version, your algorithm will also be run against "sample-laser-radar-measurement-data-2.txt". The RMSE for the second data set should be <=[0.20, 0.20, 0.55, 0.55].	
Follows the Correct Algorithm	
Your Sensor Fusion algorithm follows the general processing flow as taught in the preceding lessons.	Implemented most of the code from lesson quizzes
Your Kalman Filter algorithm handles the first measurements appropriately.	Between 106 - 147

Your Kalman Filter algorithm first predicts then updates.	Between lines 149 - 494
Your Kalman Filter can handle radar and lidar measurements.	Both used