Look at my Udacity Project Feedback!

Project Specification

Unscented Kalman Filters

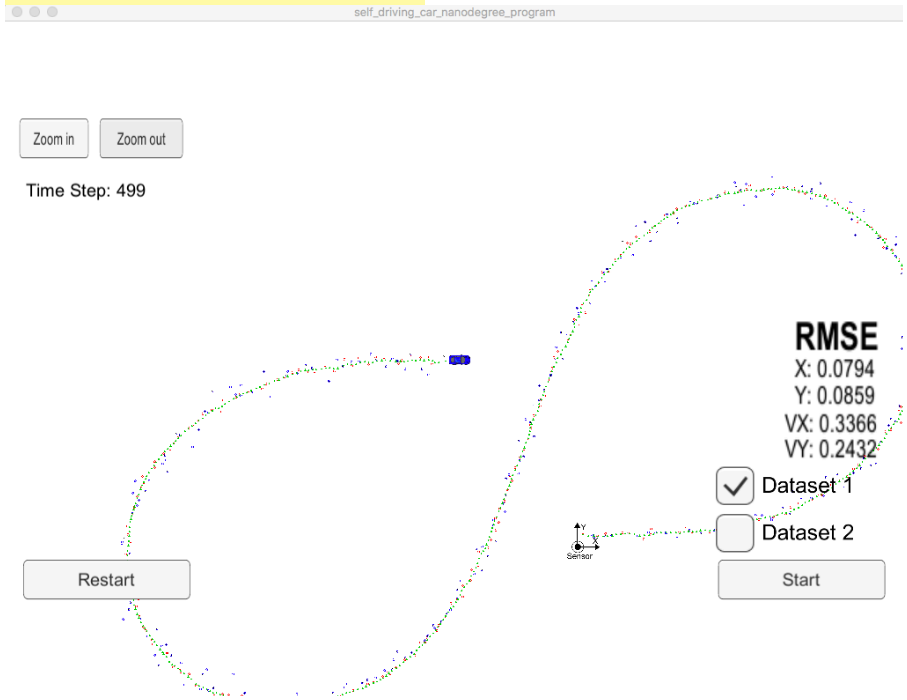
Compiling

CRITERIA	MEETS SPECIFICATIONS
Your code should compile.	Code must compile without errors with `cmake` and `make`. Given that we've made CMakeLists.txt as general as possible, it's recommended that you do not change it unless you can guarantee that your changes will still compile on any platform. Code Complies with no issues

Accuracy

	MEETS SPECIFICATIONS

CRITERIA	
The project recently changed. If you developed your project with the old version, you can still turn turn in the project with the old data sets, and your review will be based on the old criteria.	
For the new version of the project, there is now only one data set "obj_pose-laser-radar-synthetic-input.txt". px, py, vx, vy output coordinates must have an RMSE <= [.09,	For the new data set, your algorithm will be run against "obj_pose-laser-radar-synthetic-input.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 [.09, .10, .40, .30].

.10, .40, .30] when using the file: "obj_pose-laser-radar-synthetic-input.txt" If you are using the older version of the project with two data sets, criteria for passing are: that the px, py, vx, vy output coordinates have an RMSE <=[0.09, 0.09, 0.65, 0.65] when using the file: "sample-laser-radar-measurement-data-1.txt" that the px, py, vx, vy output coordinates have an RMSE	New dataset was used RMSE is [0.0794, 0.0859, 0.3366, 0.2432] which is less than above values 

<=[0.20, 0.20, 0.55, 0.55] when using the file: "sample-laser-radar-measurement-data-2.txt"	

Follows the Correct Algorithm

CRITERIA	MEETS SPECIFICATIONS
Your Sensor Fusion algorithm follows the general processing flow as taught in the preceding lessons.	While you may be creative with your implementation, there is a well-defined set of steps that must take place in order to successfully build a Kalman Filter. As such, your project should follow the algorithm as described in the preceding lesson. Followed the lessons
Your Kalman Filter algorithm handles the first measurements appropriately	Your algorithm should use the first measurements to initialize the state vectors and covariance matrices. Done

appropriately.	
Your Kalman Filter algorithm first predicts then updates.	Upon receiving a measurement after the first, the algorithm should predict object position to the current timestep and then update the prediction using the new measurement. Done
Your Kalman Filter can handle radar and lidar measurements.	Your algorithm sets up the appropriate matrices given the type of measurement and calls the correct measurement function for a given sensor type. Done

Code Efficiency

CRITERIA	MEETS SPECIFICATIONS
Your algorithm should avoid unnecessary calculations.	This is mostly a "code smell" test. Your algorithm does not need to sacrifice comprehension, stability, robustness or security for speed, however it should maintain good practice with respect to calculations.

	Here are some things to avoid. This is not a complete list, but rather a few examples of inefficiencies. • Running the exact same calculation repeatedly when you can run it once, store the value and then reuse the value later. • Loops that run too many times. • Creating unnecessarily complex data structures when simpler structures work equivalently. • Unnecessary control flow checks. Conforms to above rules. Suggestions are welcome

Suggestions to Make Your Project Stand Out!

1. While we're giving this project to you with starter code, you are not actually required to use it! If you think you can organize your Kalman Filter better than us, go for it! Also, this project was templatized in an object-oriented style, however it's reasonable to build a Kalman Filter in a functional style. Feel free to start from scratch with a functional algorithm!

    - Keep in mind that your code *must* compile. If your changes necessitate modifying CMakeLists.txt, you are responsible for ensuring that *any* reviewer can still compile your code given the dependencies listed earlier in the instructions - platform specific errors will *not* be debugged by graders.

2. There is some room for improvement with the Kalman Filter algorithm. Maybe some aspects of the algorithm could be combined? Maybe some could be skipped under certain circumstances? Maybe there are other ways to improve performance? Get creative!

3. Compare your results when only using radar or only using lidar. Sensor fusion should give better results than using only one sensor type.

4. Go back to your extended Kalman filter project and compare the results. RMSE should be lower for the unscented Kalman filter especially for velocity. The CTRV model is more precise than the constant velocity model from the EKF lectures. And UKF is also known for handling non-linear equations better than EKF.

Student FAQ