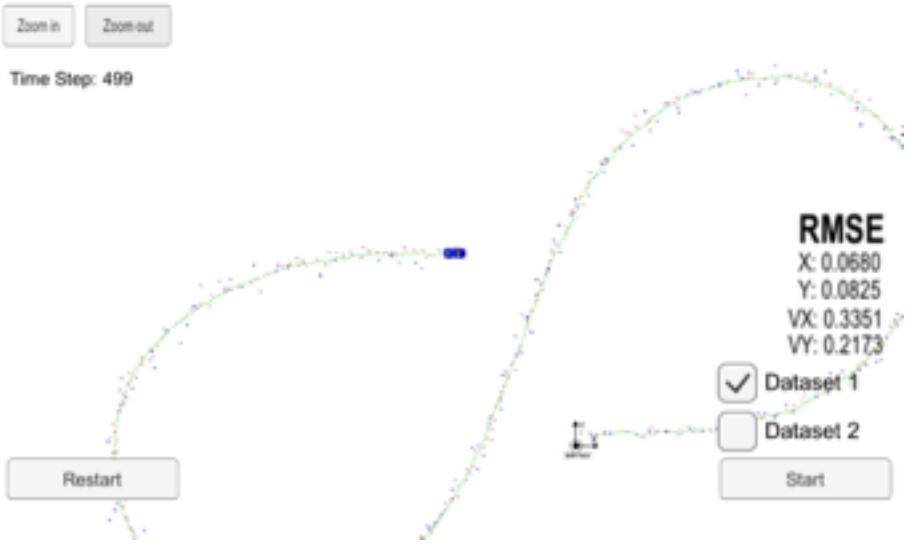
Q. Your code should compile.

A. Code compiles and predicts well.

Q. 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].

A. Parameters met.



Q. Your Sensor Fusion algorithm follows the general processing flow as taught in the preceding lessons.

A. The algorithm used is that taught in the lessons. Some of the code from the lessons is used for implementation.

Q. Your Kalman Filter algorithm handles the first measurements appropriately.

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A. The first measurements have been used to appropriately initialize state vectors. Covariance matrices have also been appropriately initialized. Other parameters were also initialized based on the need of the problem.

Q. Your Kalman Filter algorithm first predicts then updates.

A. The algorithm predicts and then updates.

Q. Your Kalman Filter can handle radar and lidar measurements.

A. The correct measurement is called and appropriate noise matrices are called for the respective sensors.

Q. Your algorithm should avoid unnecessary calculations.

A. Achieved.