UDACITY

< Return to Classroom

Joy Ride

REVIEW

CODE REVIEW

HISTORY

Meets Specifications

I have completed other programs, but I am most excited about this program !

Superb work Sho Nakamura! You have made a good choice by selecting this program as it introduces to the exciting field of autonomous vehicles, what goes on behind this technology and paves a way for advanced self driving car engineer course.

Congratulations on meeting all the project specifications.🎉

Your approach is right and in this project, the control function has to be updated as per understanding of ego car's position in the simulator. The work done demonstrates a good understanding of the concepts covered in the project. Continue with this hard work and good luck moving forward.

Reference links for learning purpose

Check out this YouTube video on how to parallel park. You can also check out this git implementation of a Car Parking system in python.

Successful Completion of Maneuvers

The `park` function causes the car to parallel park in the right lane without going off the road or hitting any of the other vehicles.

Nice job. Your code was clearly separated into sections based on the different steps for parallel parking and your car didn't even come close to hitting anything.

Extra Tip

Here is another short and effective code tip to parallel park the car in the right lane without getting in contact with any car or going off the road.

```
car_parameters = {"throttle": 0, "steer": 0, "brake": 0}


def control(pos_x, pos_y, time, velocity):
    """ Controls the simulated car"""
    global car_parameters


    if(time < 3):
        car_parameters["throttle"] = 1.0
        car_parameters["steer"] = 0.0
        car_parameters["brake"] = 0
```

```
    elif(pos_y > 41):
        car_parameters["throttle"] = -1.0
        car_parameters["steer"] = 0
        car_parameters["brake"] = 0
    elif(pos_y > 36):
        car_parameters["throttle"] = -1.0
        car_parameters["steer"] = 1.0
        car_parameters["brake"] = 0
    elif(pos_y > 32):
        car_parameters["throttle"] = -1.0
        car_parameters["steer"] = -1.0
        car_parameters["brake"] = 0
    else:
        car_parameters["throttle"] = 0
        car_parameters["steer"] = 0
        car_parameters["brake"] = 1


    return car_parameters

import src.simulate as sim
sim.run(control)
```

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