



PROJECT

PID Controller

A part of the Self-Driving Car Program

PROJECT REVIEW

CODE REVIEW 3

NOTES

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Meets Specifications

Compilation

Code must compile without errors with `cmake` and `make`.

Given that we've made CMakeLists.txt as general as possible, it's recommend that you do not change it unless you can guarantee that your changes will still compile on any platform.

Good job your code compiles and links correctly with `cmake` and `make`

Implementation

It's encouraged to be creative, particularly around hyperparameter tuning/optimization. However, the base algorithm should follow what's presented in the lessons.

good job implementing the basic PID algorithm and twiddle.

Reflection

Student describes the effect of the P, I, D component of the PID algorithm in their implementation. Is it what you expected?

Visual aids are encouraged, i.e. record of a small video of the car in the simulator and describe what each component is set to.

You did a great job at describing the effect of every component of the PID controller.

Student discusses how they chose the final hyperparameters (P, I, D coefficients). This could be have been done through manual tuning, twiddle, SGD, or something else, or a combination!

Simulation

No tire may leave the drivable portion of the track surface. The car may not pop up onto ledges or roll over any surfaces that would otherwise be considered unsafe (if humans were in the vehicle).

YOur car drives through the track! Excellent.

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