The dataset used for this assignment was Wall-Following Robot Navigation Data from UCI MLR website. This data contained 5456 observations of 24 ultrasound sensors surrounding robots as they navigated around a wall. One class label was defined for where the robot should be moving to follow the wall and will be what the RandomForestClassifier will try to be predicting. The sensors were reading at a rat of 9 samples per second, resulting in about 10 minutes of sensor data. Each sensor was placed in a 15-degree difference from the last sensor starting with the front of the robot at 180 degrees and spanning the full 360 degrees around it. This sensor data represents where the robot is and gives information about where objects are compared to the robot, in this case, the wall it is trying to follow. A random forest classifier will be fit on training data and tested on testing data to determine if it can provide the robot with the correct class of direction to move. Streaming this information could be useful for communication with other robots that do not have the sensor data but may also want to follow the same path as the sensor robot. Once the data was loaded in with the correct schema and check for no null or malformed data, the randomforestclassifier can be fitted with the training data. Running a prediction on the training data show high accuracy scores of 0.9736. Then the testing data can be transformed on the model to determine its ability to accurately predict unseen data, and once again the testing data showed a high accuracy score of 0.9665 implying the model is significantly accurate enough to predict the class of direction based on the 24 UV sensor data. The model is then streamed to demonstrate the results of testing data on the model. SQL commands can be ran to see the results of the testing prediction and with some configuring an accuracy/precision/f1/recall can be made on that streamed information.