Quest Rubric No: 5	**2**		
Objective criteria (0/1, 1=met)	**Rating**	**Max**	**Comments**
Controls steering to maintain center of course +/- 25cm for entire length	1	1	Not running right now (live). Not shown in video
Uses PID for speed control holding a fixed speed setpoint after startup and before slowdown [0.1-0.4 m/s]	1	1	Trying to maintain 0.5m/s - not running now at all (live). Works in video
Stops within 20 cm of end without collision	1	1	Looks for object at 50cm, then starts slowing until it reaches 20cm and stops - not running at all now (live). Works in video
Start and stop instructions issued wirelessly from phone, laptop or ESP)	1	1	
Measures wheel speed or distance	1	1	Demonstrated measuring wheel speed by turning the wheels by hand
Uses alpha display to show current distance or speed	1	1	Demonstrated displaying wheel speed by turning the wheels by hand
Successfully traverses A-B in one go, no hits or nudges	0.0	1	Not seen in video
Total objective criteria	**6.0**	**7**	

Qualitative criteria	**Rating**	**Max**	**Comments**
Quality of solution	3	5	5 sensors: 1 front and 1 at each corner - the sensors stopped providing input and the code does not run the car at all right now (seems like they might have too many sensors); will work to simplify the sensors and get everything working for the video. Design is reasonable, but need to tie it all together in one run.
Quality of report.md including use of graphics	3	3	
Quality of code reporting	3	3	
Quality of video presentation	3	3	Good video.
Total qualitative criteria	**12**	**14**	

Quant Weight (75)	64	75
Qual Weight (25)	21	25
Total Score	**86**	100
Rank (1-5)	4	5

Comments

PIDs on each sensor. Might be overkill. Steering and range demoed in the video. Good. But not showing complete run