1. Explain how a lane detection system works? How can it apply for curves and hills?
2. How to handle the situation that your robot see an object but don’t know what it is?
3. What approach you will use if the various sensors you are using have different refresh rates?
4. How does feature from SIFT, SURF, and HOG differ? Explain how they works and how will you apply them in perception pipeline.
5. What is voxel? And what is the process behind this algorithm? And why we do this for our point cloud data?