**SOLUTION REVIEW**

1. Fully visible images
   1. Our application accurately dictated and classified all the test signs. According to [1], the recognition accuracy rate obtained was 98.21% for the neural network model. Our training model used 20-50 epochs whereas the neural network trained in [1] used 500 epochs. Our selection of epochs was done considering the time factor. Using less than 20 epochs lead to a low confidence value while using 50 epochs modeled an overfitting graph. Incorrect recognition in [2] occurs due to several factors that include the requirement of large sets of images and all the traffic sign data is used for training purposes. Since our application used a comparatively smaller dataset, recognition accuracy was better.
2. Signs on a angle
   1. Viewing the traffic sign from different angles did not affect the recognition accuracy of the application. Shape based algorithms such as Hough Transformation, similarity detection, etc. are implemented in [6]. Kalman filter has been leveraged to detect traffic signs in video frames pursued in real-time.
3. Poor visibility
   1. Poor quality of test image can lead to some of the images not being recognised. In [4], A Laplacian of Guassian filter can be used. The main aim of this filter is to detect edges of the signs and smoothen the image.
4. Distance test
   1. Our application could only detect traffic lights within the distance of two cars lengths. The algorithm that calculates the distance in [3] attains a minimum identification of 19cm and a maximum of 61cm. The whole length of the car is considered as a metric in this case.

**Recommendations**

* GPUs can be integrated to decrease computation time.
* Larger dataset can be implemented to identify less well-known datasets.
* A system to recognise road signs while the car is travelling at a high speed is required.
* Maximum distance of recognition should also be considered in order to provide sufficient amount of time to the car to make a decision in real-time.

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