

PROJECT

Finding Lane Lines on the Road

A part of the Self Driving Car Engineer Nanodegree Program

PROJECT REVIEW

NOTES

SHARE YOUR ACCOMPLISHMENT!  

Meets Specifications

Hello,

Good work overall, you did a good job with your pipeline, Keep this up 😊

Congratulations, on meeting all of the specifications and good luck with your Self Driving Car Nanodegree. 🙌

Required Files

The project submission includes all required files



Lane Finding Pipeline

The output video is an annotated version of the input video.



Good job providing an annotated output video.

In a rough sense, the left and right lane lines are accurately annotated throughout almost all of the video. Annotations can be segmented or solid lines



Your pipeline is pretty good, with resulting lines right on target.

Visually, the left and right lane lines are accurately annotated by solid lines throughout most of the video.



The left and right lane lines are accurately annotated throughout most of the video. Well done!!

Your parameters look good, yet you may try one optimal possible set of parameters which might not create much difference your current output but will be helpful in certain conditions like curved lanes, shadows etc.

- `max_line_gap` that defines the maximum distance between segments that will be connected to a single line.
- `min_line_len` that defines the minimum length of a line that will be created.
- `min_line_len` (~100) and `max_line_gap` (~160) for Hough Transform will make your lines longer and will have less number of breaks.(this will make the solid annotated line longer in the output)Increasing `max_line_gap` will allow points that are farther away from each other to be connected with a single line.
- Decreasing the `kernel-size` in the Gaussian Filter might also help, as this will remove the noise making the image less blurry.
- Consider using `rho` value of 2 (`rho` , distance resolution of the Hough accumulator in pixels.)

For further reading and references:

[link1](#)[link2](#)[link3](#)[link4](#) for optional video.

Reflection



Reflection describes the current pipeline, identifies its potential shortcomings and suggests possible improvements. There is no minimum length. Writing in English is preferred but you may use any language.

Great addition in the reflection section rubric about how the pipeline would have trouble identifying curved lanes and shadows!

Since the algorithm is "trained" on a very specific road and light conditions when these conditions change we can expect that the algorithm performance will degrade.

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