

# Multi-sensor rail track detection in automatic train operations

Master's thesis in Data Science

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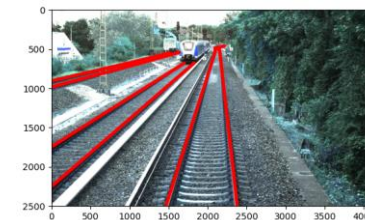
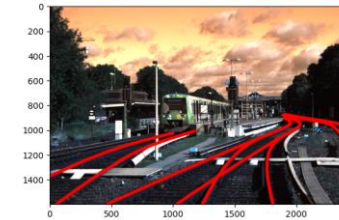
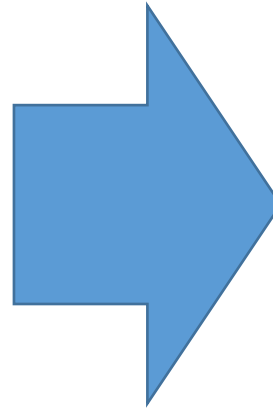
Alignment: 17.01.2024



# Problem setting

## What is Automatic train operations (ATO)

Technology is used to automate tasks that were previously performed by rail personnel (e.g., conductor)

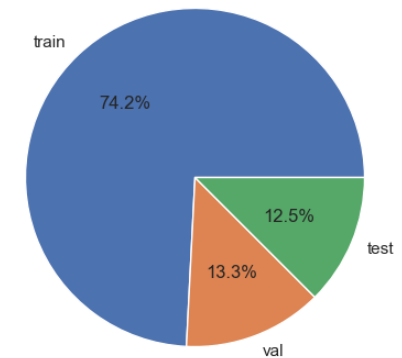


# Dataset

- Deutschbahn:
  - Multisensor dataset
    - Infrared
    - RGB 5MP
    - RGB 12MP
    - Left, right, and center, respectively
  - Large similarity between frames of video → split on videos



Data split: train, validation, test



# Modelling rail detection as segmentation

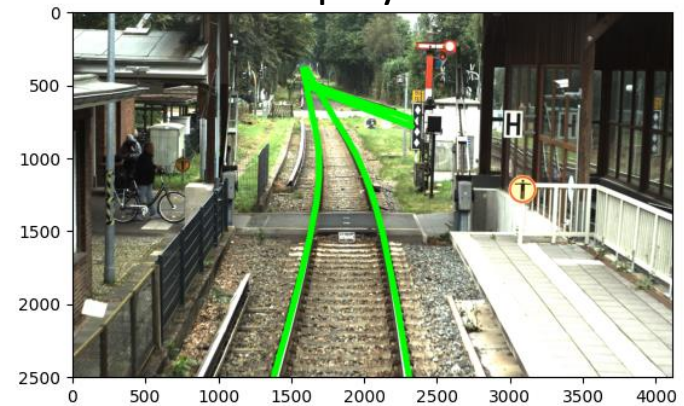
- Semantic segmentation → deep learning algorithm that associates a label or category with every pixel in an image
- Distinguish background pixels and track pixels
- In the data tracks are annotated by lines rather than pixel masks

# Modelling rail detection as segmentation

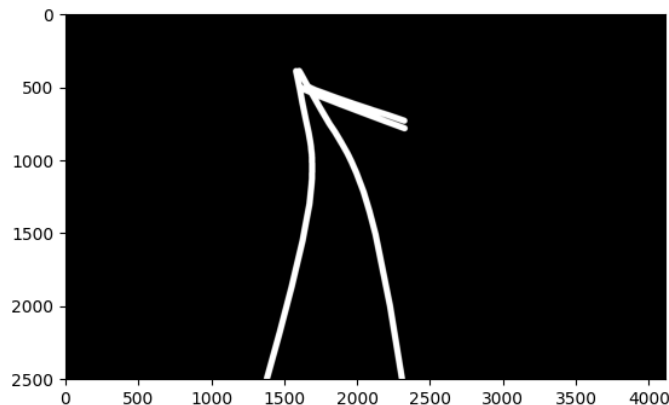
Original image



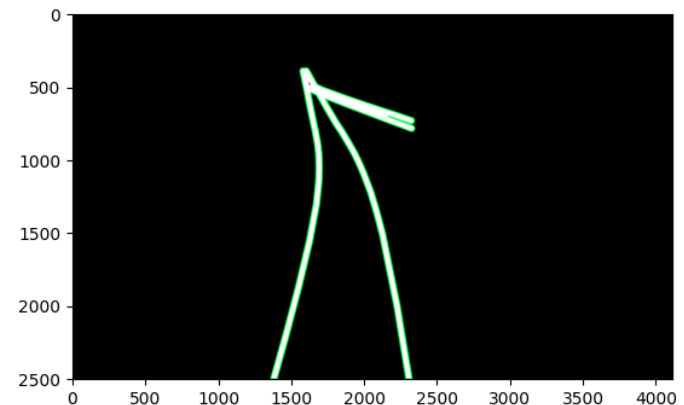
Thick polylines



Mask

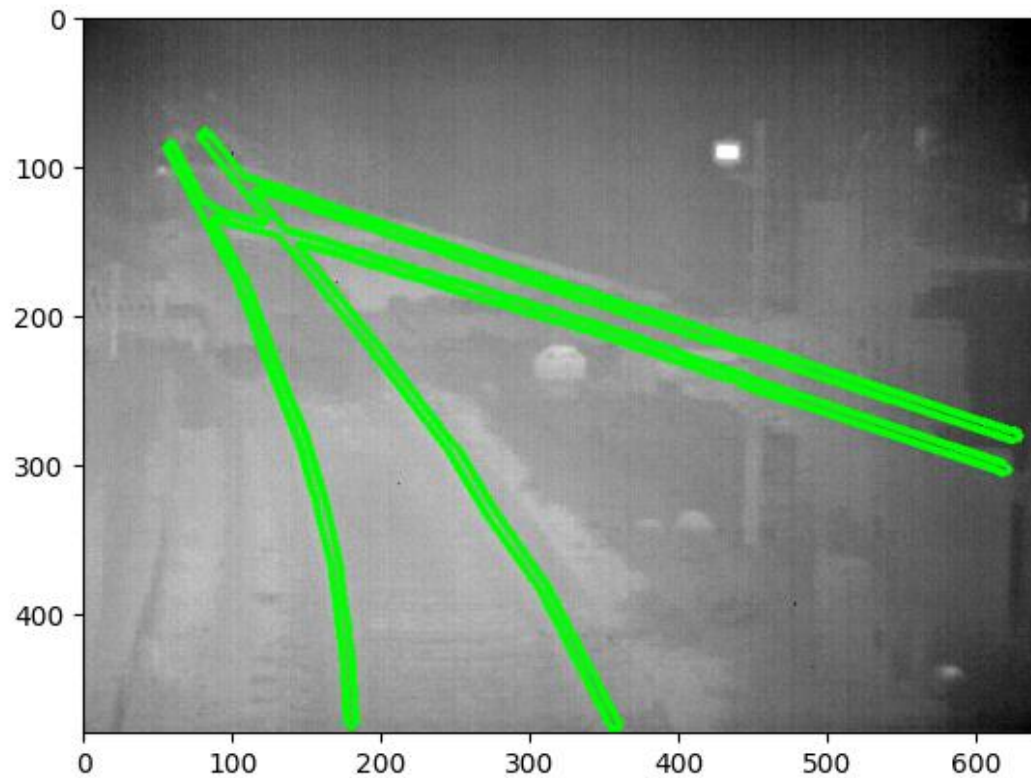


Mask with contour

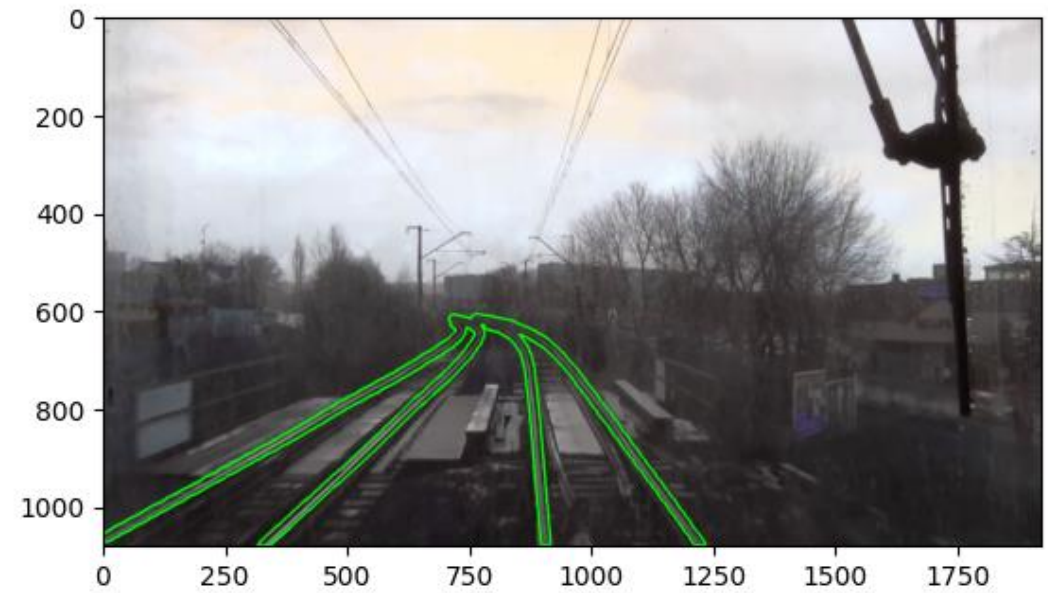


# Modelling rail detection as segmentation

Example IR



Example RailSem



# Performance metrics

## Precision

Of all **positive predictions**,  
how many are **really positive**?

$$\frac{TP}{TP + FP}$$

		Real Class	
		Positive	Negative
Predicted Class	Positive	TP	FP
	Negative	FN	TN

## Recall

Of all **real positive cases**,  
how many are **predicted positive**?

$$\frac{TP}{TP + FN}$$

		Real Class	
		Positive	Negative
Predicted Class	Positive	TP	FP
	Negative	FN	TN

Zera, 2021

$$Precision = \frac{TP}{TP + FP}$$

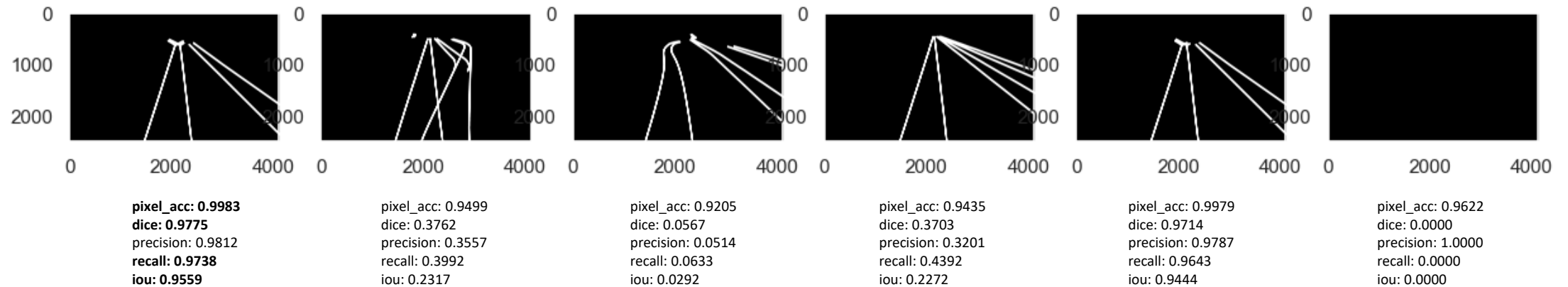
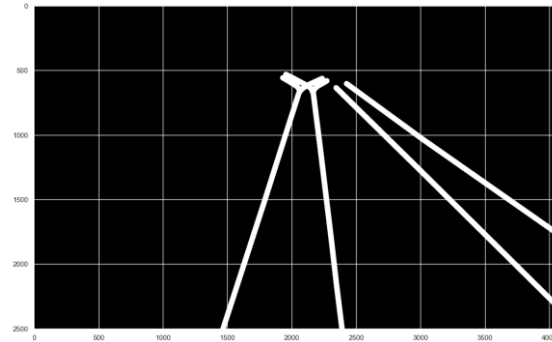
$$Recall = \frac{TP}{TP + FN}$$

$$Accuracy = \frac{TP + TN}{TP + TN + FN + FP}$$

$$Dice = \frac{2TP}{2TP + FP + FN}$$

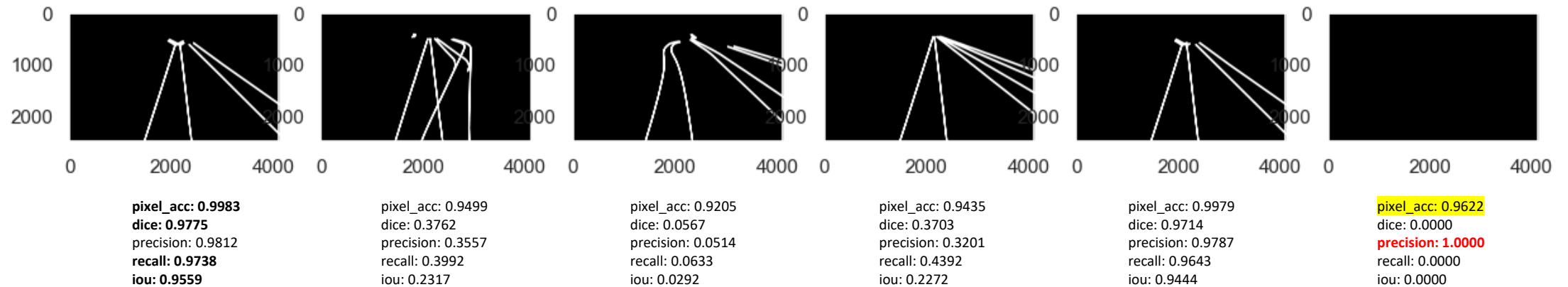
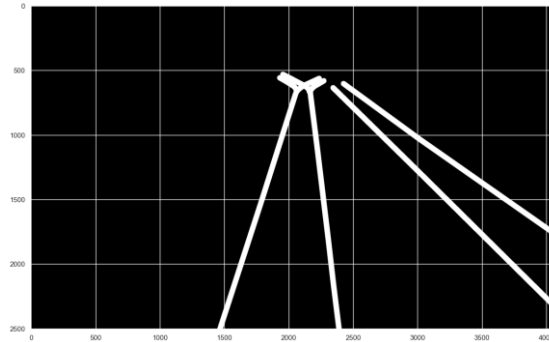
$$IoU = \frac{TP}{TP + FP + FN}$$

# Performance metrics



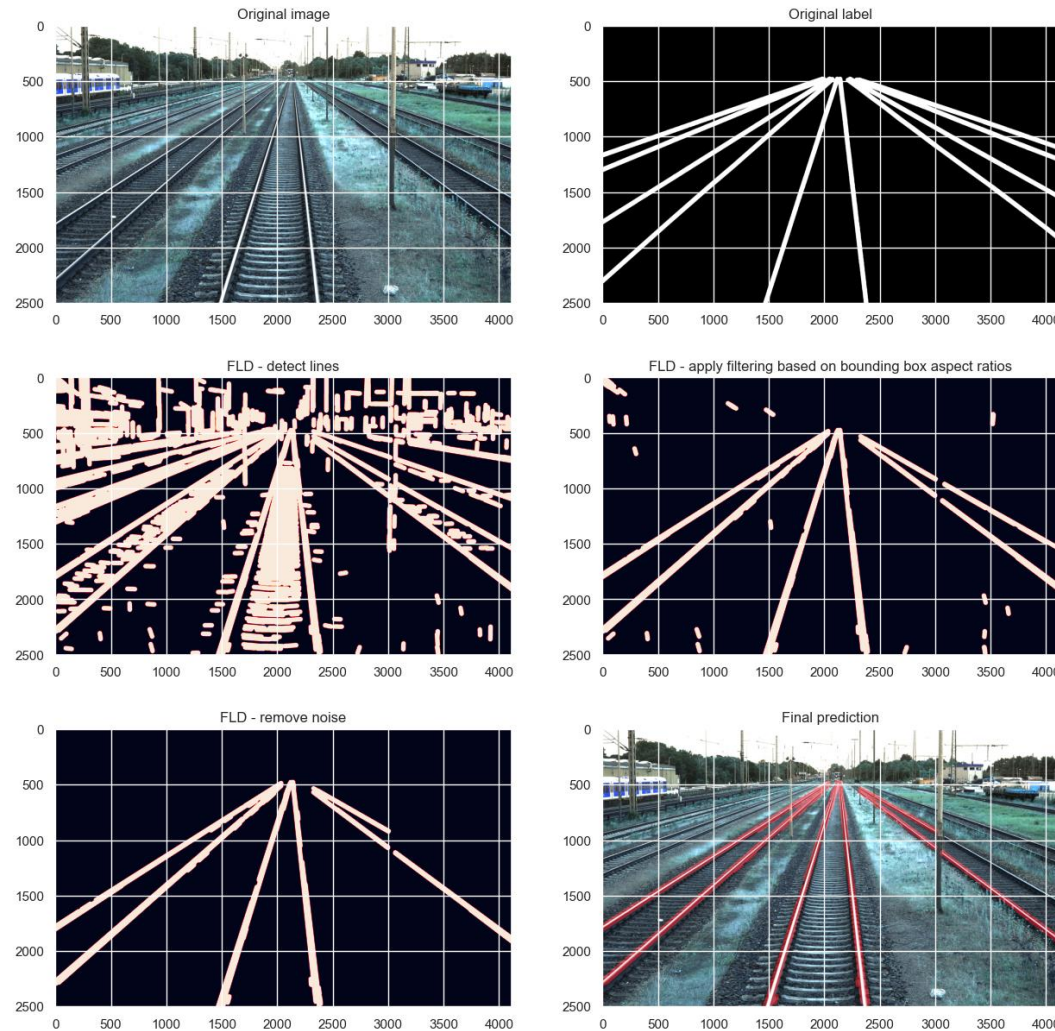


# Performance metrics



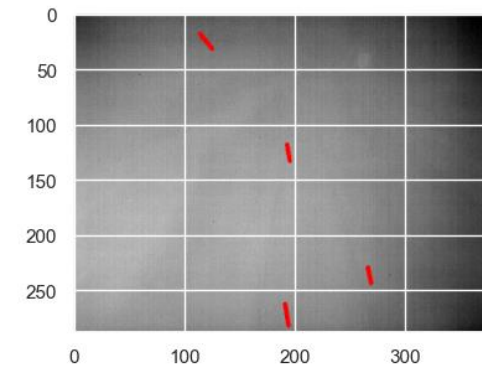
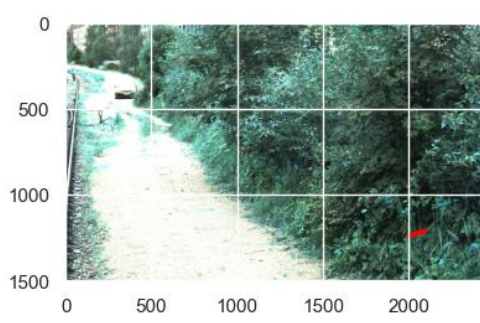
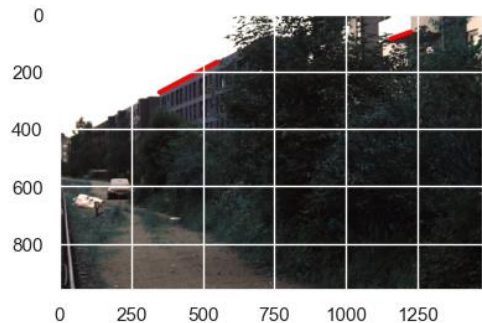
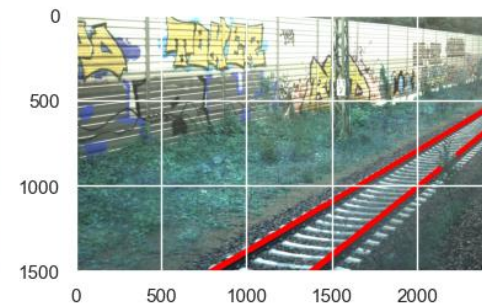
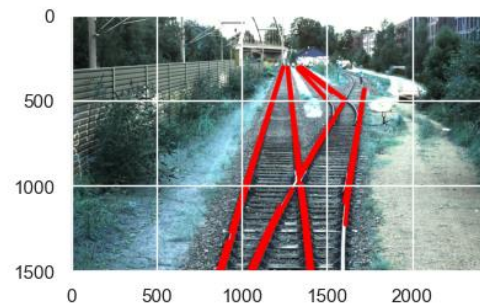
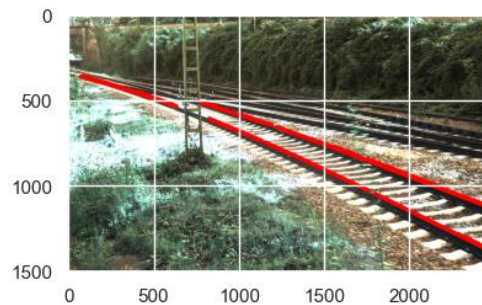
$$\text{precision} = (\text{tp} + \text{self.eps}) / (\text{tp} + \text{fp} + \text{self.eps})$$

# Baselining with fast line detection



# Baselining with fast line detection

## Good examples and bad examples



# Deep learning approach

- YOLOv8 as framework
- Can be used for segmentation and object detection
- State-of-the-art computer vision model built by Ultralytics
- Easy to use
- Open source

# YOLO experiments

- Model backbone: yolov8n-seg
- Combined loss function consisting of
  - bounding box loss (error between the predicted and the ground truth boxes' geometry)
  - objectness loss (how confident the model is about the presence of an object in the bounding box)
  - segmentation loss (how close the predicted segmentation map is to the ground truth map)
- Parameters
  - epochs: 300
  - image size: 640, 1280 (where applicable)
  - batch size: auto selection based on image size and available memory
  - Yolo defaults
- Logging: Comet ML



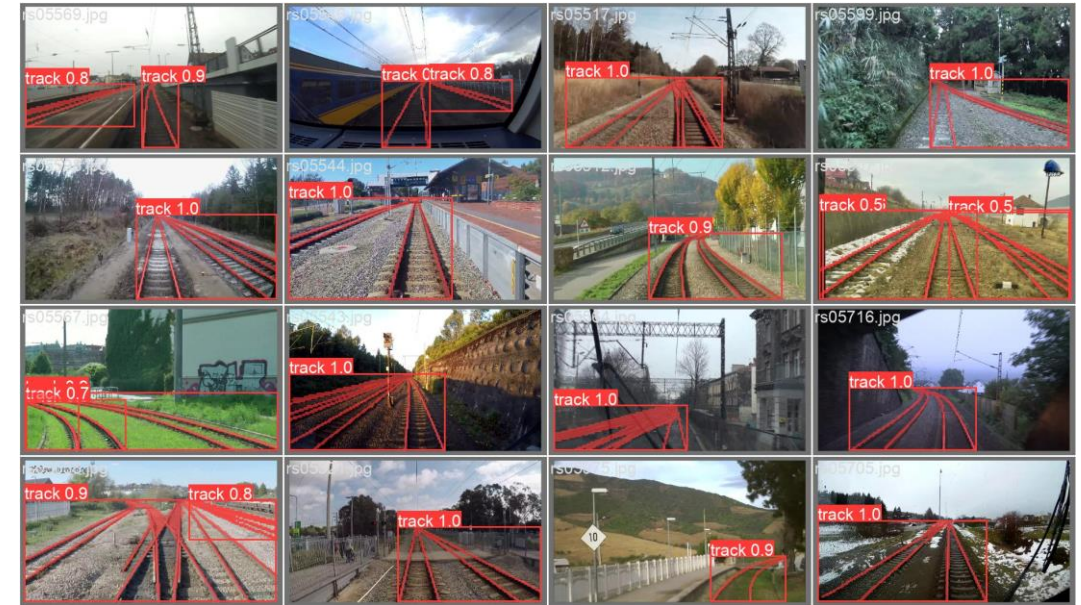
# YOLOv8

## First experiments - RGB

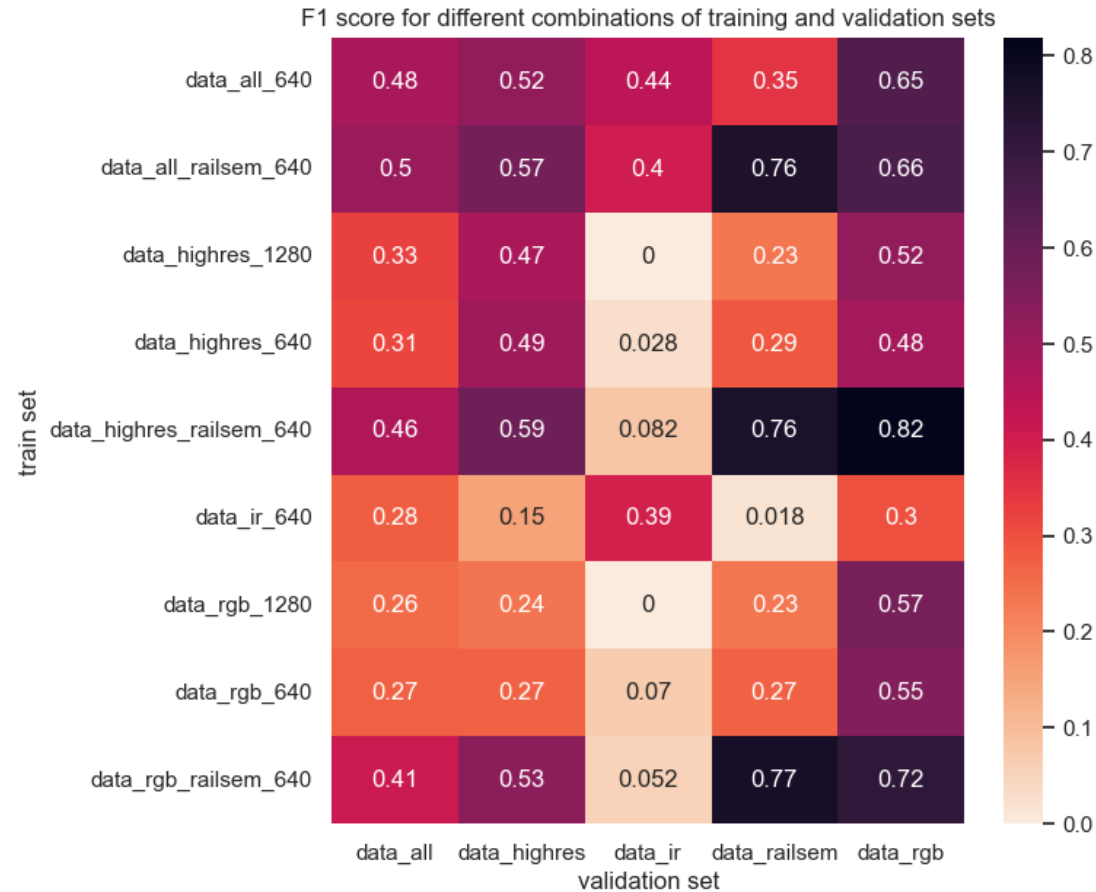
Without RailSem data



With RailSem data

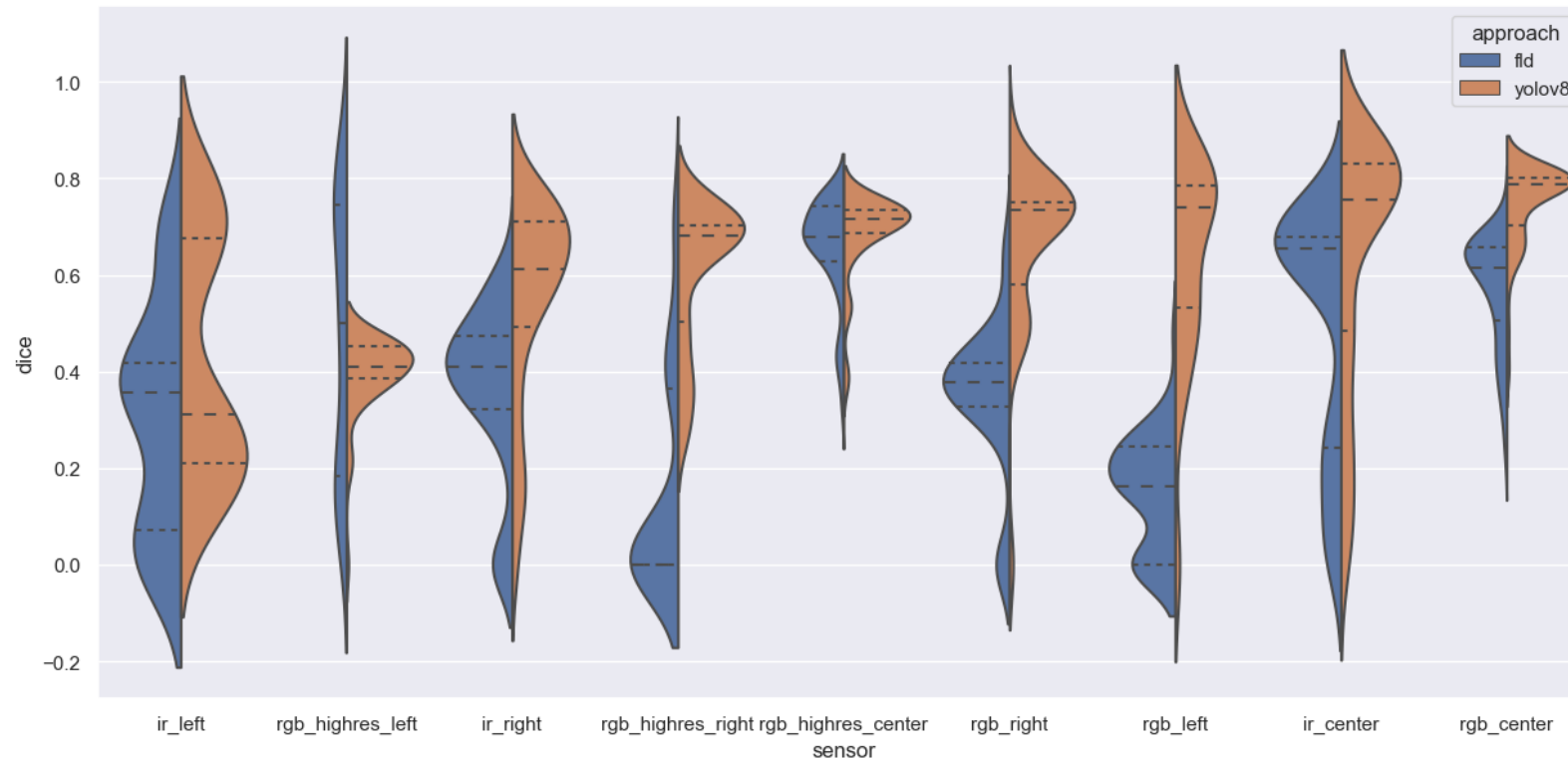


# 9 models have been trained and validated



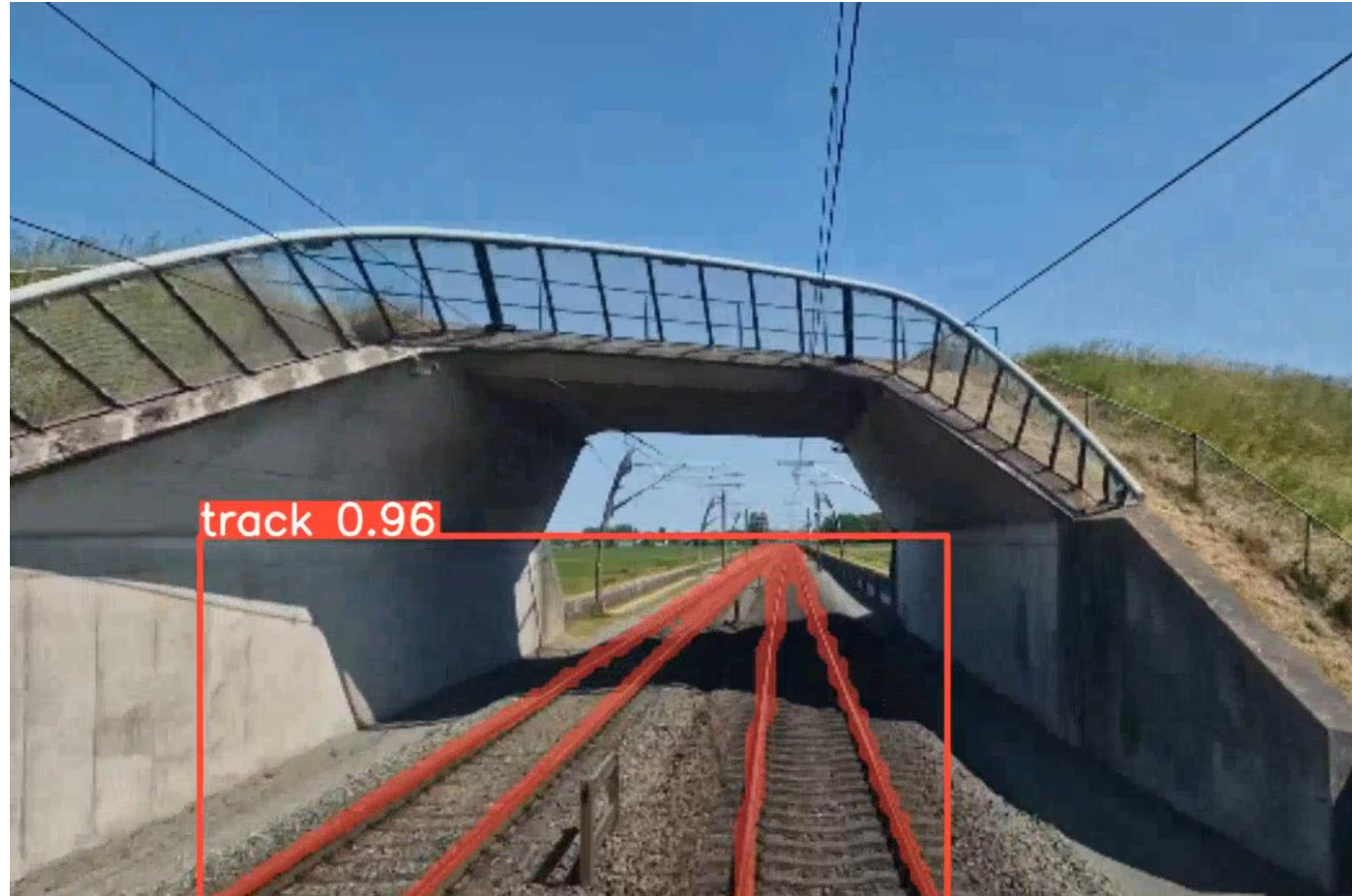
# YOLOv8 vs FDL

## Performance on **validation** data





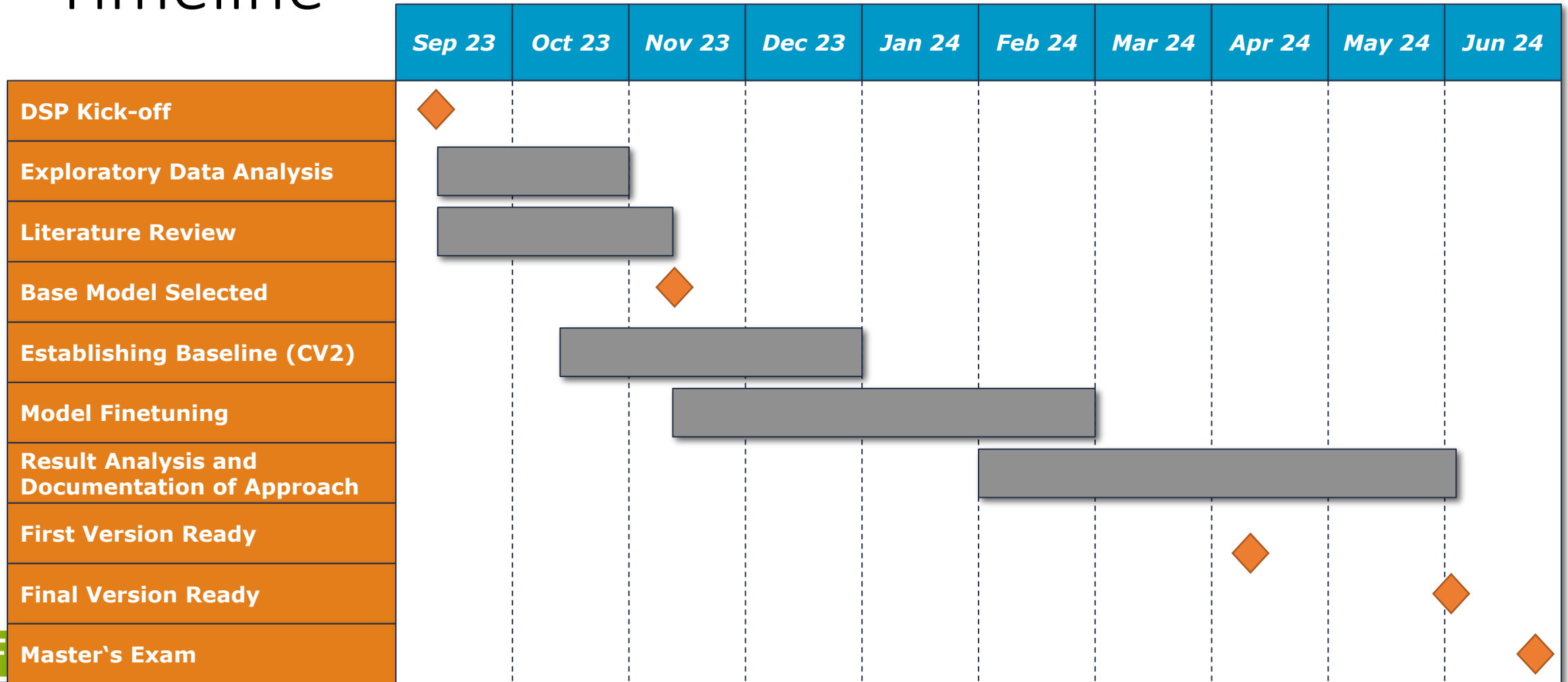
# DEMO



# Conclusion

- Image segmentation seems to be a proper approach for modelling and solving the rail track detection problem
- Dice or f1 are well suited to assess the performance of different segmentation approaches
- Fast line detection provides a solid baseline, however YOLO outperforms FDL in most scenarios
- It seems that the performance across different sensors is similar – the orientation of the sensors has a larger impact on the results
- YOLO is well suited to be applied in real life due to fast inference

# Timeline



Thank you!