# Machine Learning Week 5 Progress Report

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This week, we implemented the acceleration directional function - After group discussion and consulting with the professor, we decided to implement the acceleration angle rather than an azimuth angle. We are using the acceleration angle of all the vehicles at a given time to ultimately calculate the edge of the road.

We are continuously working on writing the new logic of the algorithm to define the edge of the road and then working on lane detection.

References

1. Barmpounakis, Emmanouil, Guillaume M. Sauvin, and Nikolaos Geroliminis. "Lane detection and lane-changing identification with high-resolution data from a swarm of drones." Transportation research record 2674.7 (2020): 1-15.