

## PROJECT

### Finding Lane Lines on the Road

A part of the Self Driving Car Engineer Nanodegree Program

#### PROJECT REVIEW

#### NOTES

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Meets Specifications

#### Lane Finding Pipeline

The output video is an annotated version of the input 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

Good job on the model!

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

Good job on the model! Good job filtering out horizontal hough lines with:

```
if -maxslope < m < -minslope:
    iside = 0
elif minslope < m < maxslope:
    iside = 1
else:
```

Another optional preprocessing some students have done is HSV transformation. We can extract only the white and yellow colors through setting up a lower and upper color bound and thresholding the HSV image to only extract yellow and white colors. This can extract much of the yellow and white colors of the image and help the performance of the challenge problem. This link is an good example of this method. [http://docs.opencv.org/trunk/df/d9d/tutorial\\_py\\_colorspaces.html](http://docs.opencv.org/trunk/df/d9d/tutorial_py_colorspaces.html)

#### 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.

Good job on the reflection! Good job trying to use the previous couple frames to try to do lane smoothing. Good job in thinking that under different environments that could effect the region of interest and the current parameters to extract hough lines, the model could perform worse.

We will learn of more adaptive and autonomous models in the next lessons.

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