

P2

July 17, 2019

0.1 Advanced Lane Finding Project

The goals / steps of this project are the following:

- Compute the camera calibration matrix and distortion coefficients given a set of chessboard images.
- Apply a distortion correction to raw images.
- Use color transforms, gradients, etc., to create a thresholded binary image.
- Apply a perspective transform to rectify binary image (“birds-eye view”).
- Detect lane pixels and fit to find the lane boundary.
- Determine the curvature of the lane and vehicle position with respect to center.
- Warp the detected lane boundaries back onto the original image.
- Output visual display of the lane boundaries and numerical estimation of lane curvature and vehicle position.

```
[1]: import numpy as np
import cv2
import glob
import matplotlib.pyplot as plt
import matplotlib.image as mpimg
%matplotlib inline

import advanced_lane_line_helper_functions as aahlpf
import lane_lines_helper_functions as llhlpf
```

```
[2]: # Make a list of calibration images
images = glob.glob('camera_cal/calibration*.jpg')
```

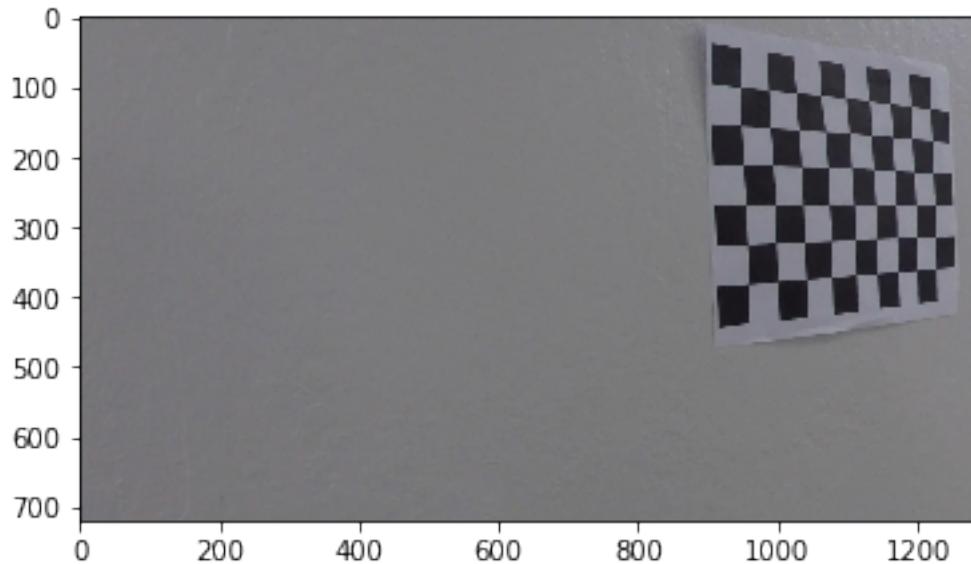
```
[3]: print(images)
```

```
['camera_cal\\calibration1.jpg', 'camera_cal\\calibration10.jpg',
'camera_cal\\calibration11.jpg', 'camera_cal\\calibration12.jpg',
'camera_cal\\calibration13.jpg', 'camera_cal\\calibration14.jpg',
'camera_cal\\calibration15.jpg', 'camera_cal\\calibration16.jpg',
'camera_cal\\calibration17.jpg', 'camera_cal\\calibration18.jpg',
'camera_cal\\calibration19.jpg', 'camera_cal\\calibration2.jpg',
'camera_cal\\calibration20.jpg', 'camera_cal\\calibration3.jpg',
'camera_cal\\calibration4.jpg', 'camera_cal\\calibration5.jpg',
'camera_cal\\calibration6.jpg', 'camera_cal\\calibration7.jpg',
'camera_cal\\calibration8.jpg', 'camera_cal\\calibration9.jpg']
```

```
[4]: img = cv2.imread(images[7])
rgb_img = cv2.cvtColor(img, cv2.COLOR_BGR2RGB)
print(rgb_img.shape)
plt.imshow(rgb_img)
```

(720, 1280, 3)

```
[4]: <matplotlib.image.AxesImage at 0x197941ae0f0>
```



0.2 Compute the camera calibration matrix and distortion coefficients given a set of chessboard images

```
[5]: # prepare object points
nx = 9 # enter the number of inside corners in x
ny = 6 # enter the number of inside corners in y

# Make a list of calibration images
img = cv2.imread(images[7])

# Convert to grayscale
gray = cv2.cvtColor(img, cv2.COLOR_BGR2GRAY)

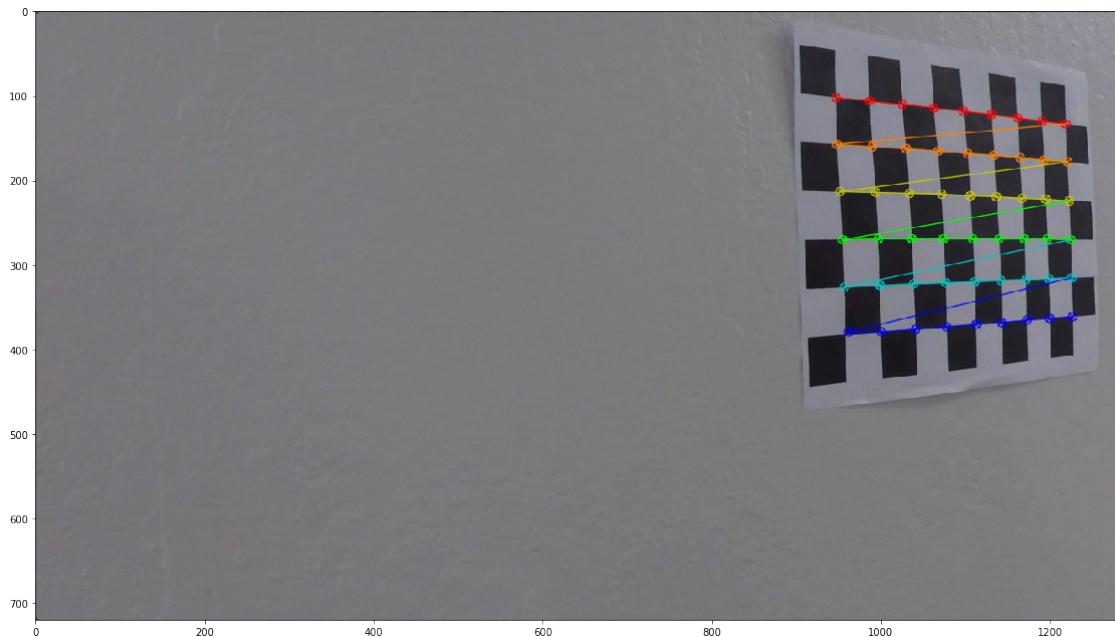
# Find the chessboard corners
ret, corners = cv2.findChessboardCorners(gray, (nx, ny), None)
```

```

# If found, draw corners
if ret == True:
    # Draw and display the corners
    cv2.drawChessboardCorners(img, (nx, ny), corners, ret)
    rgb_img = cv2.cvtColor(img, cv2.COLOR_BGR2RGB)
    # plt.imshow(img)

fig, ax = plt.subplots(figsize=(16, 9))
ax.imshow(rgb_img)
plt.tight_layout()

```



[6]: `# fig.savefig('output_images/calibration_find_corners.jpg')`

[7]: `''''`
`save_img = cv2.imread('output_images/calibration_find_corners.jpg')`
`f, ax = plt.subplots(1, 1, figsize=(24, 9))`
`f.tight_layout()`
`ax.imshow(cv2.cvtColor(save_img, cv2.COLOR_BGR2RGB))`
`plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)`
`'''`

[7]: `"\nsave_img = cv2.imread('output_images/calibration_find_corners.jpg')\nf, ax =\nplt.subplots(1, 1, figsize=(24, 9))\nf.tight_layout()\nax.imshow(cv2.cvtColor(sa\nve_img, cv2.COLOR_BGR2RGB))\nplt.subplots_adjust(left=0., right=1, top=0.9,\nbottom=0.)\n"`

[8]: `imgpoints, objpoints = aahlpf.find_cal_pts(images, nx=9, ny=6)`

```
[9]: # Read in each image
img = cv2.imread(images[7])

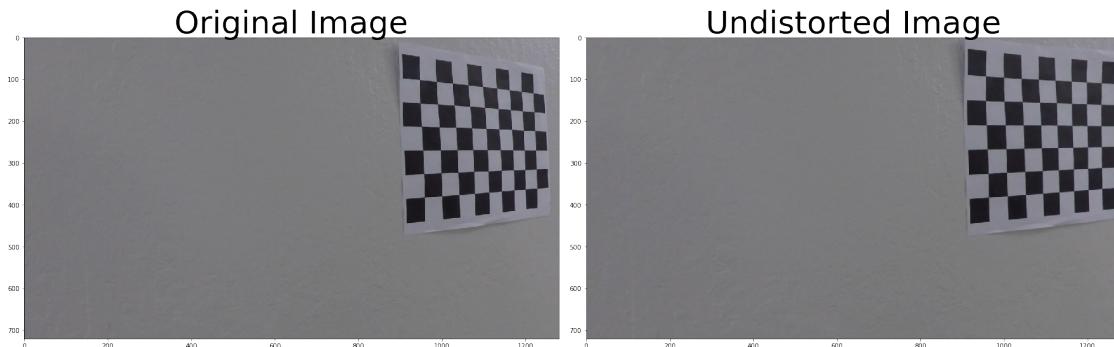
# Convert image to grayscale
gray = cv2.cvtColor(img, cv2.COLOR_BGR2GRAY)

ret, mtx, dist, rvecs, tvecs = cv2.calibrateCamera(objpoints, imgpoints,
                                                gray.shape[::-1], None, None)
```

```
[10]: # Read in each image
img = cv2.imread(images[7])

undist = cv2.undistort(img, mtx, dist, None, mtx)

f, (ax1, ax2) = plt.subplots(1, 2, figsize=(24, 9))
f.tight_layout()
ax1.imshow(cv2.cvtColor(img, cv2.COLOR_BGR2RGB))
ax1.set_title('Original Image', fontsize=50)
ax2.imshow(cv2.cvtColor(undist, cv2.COLOR_BGR2RGB))
ax2.set_title('Undistorted Image', fontsize=50)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



```
[11]: # f.savefig('output_images/calibration_distort_correct.jpg')
```

```
[12]: '''
save_img = cv2.imread('output_images/calibration_distort_correct.jpg')
f, ax = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax.imshow(cv2.cvtColor(save_img, cv2.COLOR_BGR2RGB))
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
'''
```

```
[12]: "\nsave_img = cv2.imread('output_images/calibration_distort_correct.jpg')\nf, ax
= plt.subplots(1, 1, figsize=(24, 9))\nf.tight_layout()\nax.imshow(cv2.cvtColor(
save_img, cv2.COLOR_BGR2RGB))\nplt.subplots_adjust(left=0., right=1, top=0.9,
bottom=0.)\n"
```

0.3 Apply a distortion correction to raw images

```
[13]: # Make a list of calibration images
lane_images = glob.glob('test_images/*.jpg')
```

```
[14]: print(len(lane_images))
print(lane_images)
```

8

```
['test_images\\straight_lines1.jpg', 'test_images\\straight_lines2.jpg',
'test_images\\test1.jpg', 'test_images\\test2.jpg', 'test_images\\test3.jpg',
'test_images\\test4.jpg', 'test_images\\test5.jpg', 'test_images\\test6.jpg']
```

```
[15]: im_num = 4
lane_image = mpimg.imread(lane_images[im_num])
print(lane_images[im_num])
print(lane_image.shape)
# plt.imshow(lane_image)
```

```
test_images\test3.jpg
(720, 1280, 3)
```

```
[16]: lane_undist = cv2.undistort(lane_image, mtx, dist, None, mtx)

f, (ax1, ax2) = plt.subplots(1, 2, figsize=(24, 9))
f.tight_layout()
ax1.imshow(lane_image)
ax1.set_title('Original Image', fontsize=50)
ax2.imshow(lane_undist)
ax2.set_title('Undistorted Image', fontsize=50)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



```
[17]: # f.savefig('output_images/test5_distort_correct.jpg')
```

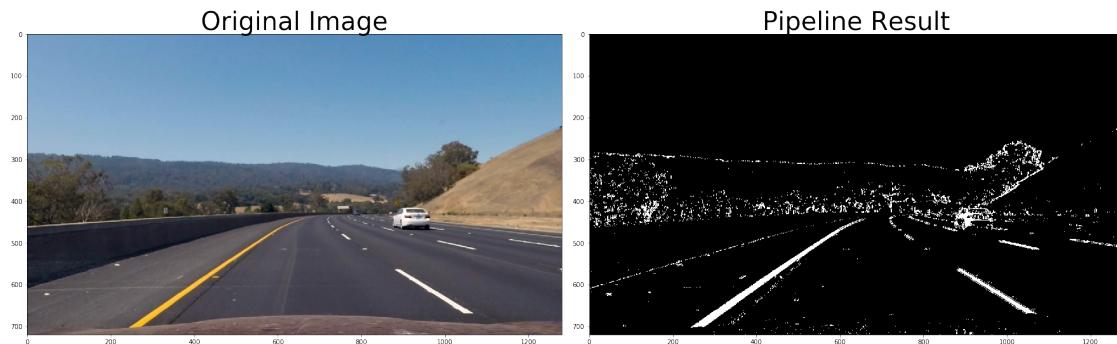
0.4 Use color transforms, gradients, etc., to create a thresholded binary image

```
[18]: result = aahlpf.pipeline(lane_undist)
```

```
[19]: # Plot the result
f, (ax1, ax2) = plt.subplots(1, 2, figsize=(24, 9))
f.tight_layout()

ax1.imshow(lane_undist)
ax1.set_title('Original Image', fontsize=40)

ax2.imshow(result, cmap='gray')
ax2.set_title('Pipeline Result', fontsize=40)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



```
[20]: # f.savefig('output_images/test5_binary.jpg')
```

```
[21]: img = lane_undist
ksize = 3
sobelx_thresh = (20, 100)

gradx = aahlpf.abs_sobel_thresh(img, orient='x', sobel_kernel=ksize,
                                 thresh=sobelx_thresh)

combined = np.zeros_like(gradx)
combined[(gradx == 1)] = 1

...
f, ax1 = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax1.imshow(gradx, cmap='gray')
```

```

plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
'''

[21]: "\nf, ax1 = plt.subplots(1, 1, figsize=(24,
9))\nf.tight_layout()\nax1.imshow(gradx,
cmap='gray')\nplt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)\n"

```

```

[22]: img = lane_undist
s_thresh = (215, 240)

hls = cv2.cvtColor(img, cv2.COLOR_RGB2HLS)
s_channel = hls[:, :, 2]

s_binary = np.zeros_like(s_channel)
s_binary[(s_channel >= s_thresh[0]) & (s_channel <= s_thresh[1])] = 1

'''
f, ax1 = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax1.imshow(s_binary, cmap='gray')
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
'''

```

```

[22]: "\nf, ax1 = plt.subplots(1, 1, figsize=(24,
9))\nf.tight_layout()\nax1.imshow(s_binary,
cmap='gray')\nplt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)\n"

```

```

[23]: img = lane_undist
r_thresh = (225, 255)

r = img[:, :, 0]

r_binary = np.zeros_like(r)
r_binary[(r > r_thresh[0]) & (r <= r_thresh[1])] = 1

'''
f, ax1 = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax1.imshow(r_binary, cmap='gray')
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
'''

```

```

[23]: "\nf, ax1 = plt.subplots(1, 1, figsize=(24,
9))\nf.tight_layout()\nax1.imshow(r_binary,
cmap='gray')\nplt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)\n"

```

```

[24]: combined = np.zeros_like(gradx)
combined[(gradx == 1)] = 1

color_combined = np.zeros_like(s_binary)

```

```

color_combined[(s_binary == 1) | (r_binary == 1)] = 1

color_binary = np.zeros_like(combined)
color_binary[(combined == 1) | (color_combined == 1)] = 1

'''
f, ax1 = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax1.imshow(color_binary, cmap='gray')
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
'''
```

[24]: "`\nf, ax1 = plt.subplots(1, 1, figsize=(24, 9))\nf.tight_layout()\nax1.imshow(color_binary,\ncmap='gray')\nplt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)\n`"

0.5 Apply a perspective transform to rectify binary image

[25]: `print(lane_images)`

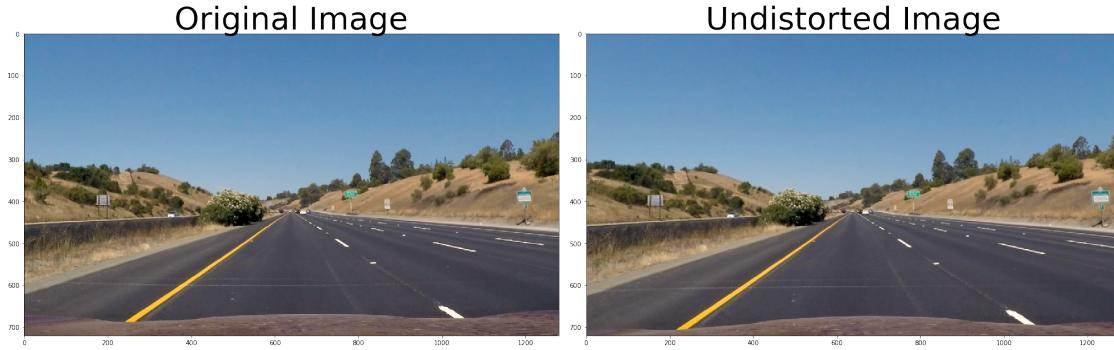
```
['test_images\\straight_lines1.jpg', 'test_images\\straight_lines2.jpg',
'test_images\\test1.jpg', 'test_images\\test2.jpg', 'test_images\\test3.jpg',
'test_images\\test4.jpg', 'test_images\\test5.jpg', 'test_images\\test6.jpg']
```

[26]: `straight_lines1 = plt.imread(lane_images[0])`
`print(straight_lines1.shape)`

(720, 1280, 3)

[27]: `straight_lines1_undist = cv2.undistort(straight_lines1, mtx, dist, None, mtx)`

```
f, (ax1, ax2) = plt.subplots(1, 2, figsize=(24, 9))
f.tight_layout()
ax1.imshow(straight_lines1)
ax1.set_title('Original Image', fontsize=50)
ax2.imshow(straight_lines1_undist)
ax2.set_title('Undistorted Image', fontsize=50)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



```
[28]: rho = 1 # distance resolution in pixels of the Hough grid
theta = np.pi/180 # angular resolution in radians of the Hough grid
threshold = 25      # minimum number of votes (intersections in Hough grid cell)
min_line_len = 25 #minimum number of pixels making up a line
max_line_gap = 25      # maximum gap in pixels between connectable line segments

[29]: trans_ratio = (80/128)
print(trans_ratio*straight_lines1.shape[0])
```

450.0

```
[30]: print(trans_ratio)
```

0.625

```
[31]: src, dst, edges = llhlpf.get_line_params_advanced(straight_lines1_undist, rho,
    ↪theta, threshold, min_line_len, max_line_gap,
    ↪trans_im_h=trans_ratio,
    ↪margin=300)

[32]: print(src)
print(dst)
```

```
[[ 205.  720.]
 [ 598.  450.]
 [ 681.  450.]
 [1116.  720.]]
[[300.  720.]
 [300.   0.]
 [980.   0.]
 [980.  720.]]
```

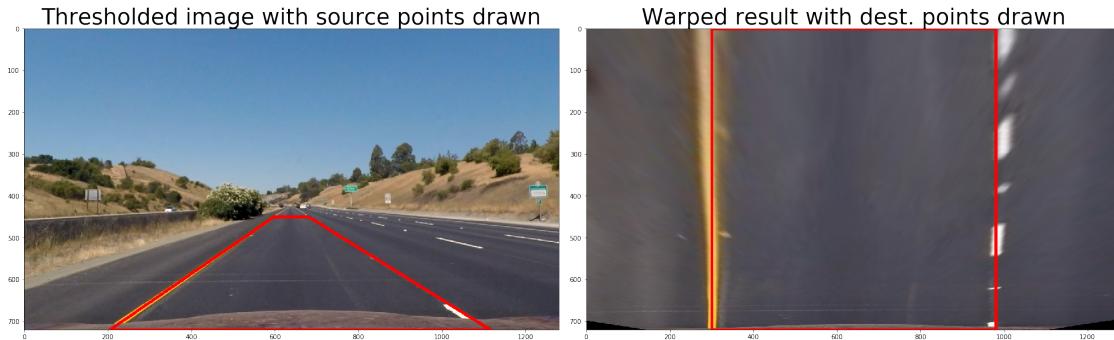
```
[33]: M = cv2.getPerspectiveTransform(src, dst)
Minv = cv2.getPerspectiveTransform(dst, src)
```

```
[34]: img_poly = straight_lines1_undist.copy()
vrx = np.int32(src)
vrx_reshape = vrx.reshape((-1,1,2))
cv2.polyline(img_poly, [vrx_reshape], True, (255, 0, 0), 5)

straight_lines1_warped = cv2.warpPerspective(
    straight_lines1_undist, M, (edges.shape[1], edges.shape[0]), flags=cv2.
    ↪INTER_LINEAR)

img_warped_poly = straight_lines1_warped.copy()
vrx_warped = np.int32(dst)
vrx_warped_reshape = vrx_warped.reshape((-1,1,2))
cv2.polyline(img_warped_poly, [vrx_warped_reshape], True, (255, 0, 0), 5)

f, (ax1, ax2) = plt.subplots(1, 2, figsize=(24, 9))
f.tight_layout()
ax1.imshow(img_poly)
ax1.set_title('Thresholded image with source points drawn', fontsize=35)
ax2.imshow(img_warped_poly)
ax2.set_title('Warped result with dest. points drawn', fontsize=35)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



```
[35]: bin_img_poly = np.dstack((result, result, result))*255
vrx = np.int32(src)
vrx_reshape = vrx.reshape((-1,1,2))
cv2.polyline(bin_img_poly, [vrx_reshape], True, (255, 0, 0), 5)

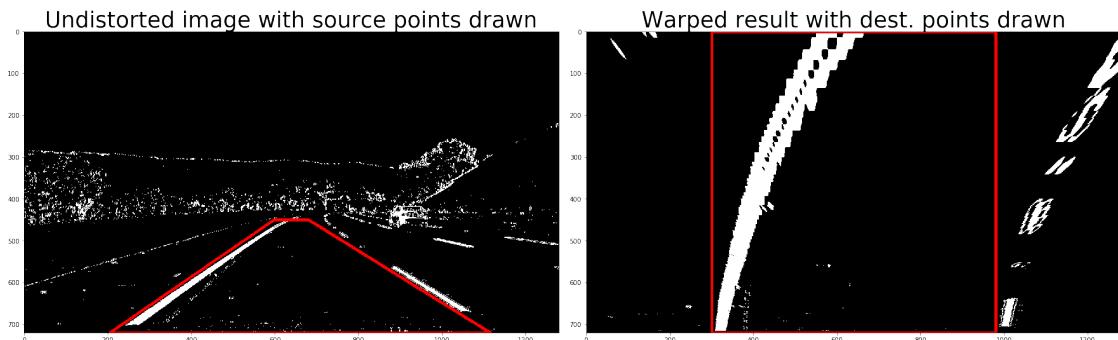
result_warped = cv2.warpPerspective(
    result, M, (result.shape[1], result.shape[0]), flags=cv2.INTER_LINEAR)

bin_img_warped_poly = np.dstack((result_warped, result_warped, ↪
    ↪result_warped))*255
vrx_warped = np.int32(dst)
vrx_warped_reshape = vrx_warped.reshape((-1,1,2))
cv2.polyline(bin_img_warped_poly, [vrx_warped_reshape], True, (255, 0, 0), 5)
```

```

f, (ax1, ax2) = plt.subplots(1, 2, figsize=(24, 9))
f.tight_layout()
ax1.imshow(bin_img_poly)
ax1.set_title('Undistorted image with source points drawn', fontsize=35)
ax2.imshow(bin_img_warped_poly)
ax2.set_title('Warped result with dest. points drawn', fontsize=35)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)

```



[36]: # f.savefig('output_images/test5_warped.jpg')

0.6 Detect lane pixels and fit to find the lane boundary

[37]: # Create histogram of image binary activations
histogram = aahlpf.hist(result_warped, h_frac=(3/4))

[38]: # Visualize the resulting histogram
'''
f, ax = plt.subplots(1, 1, figsize=(24, 9))
ax.plot(histogram)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
'''

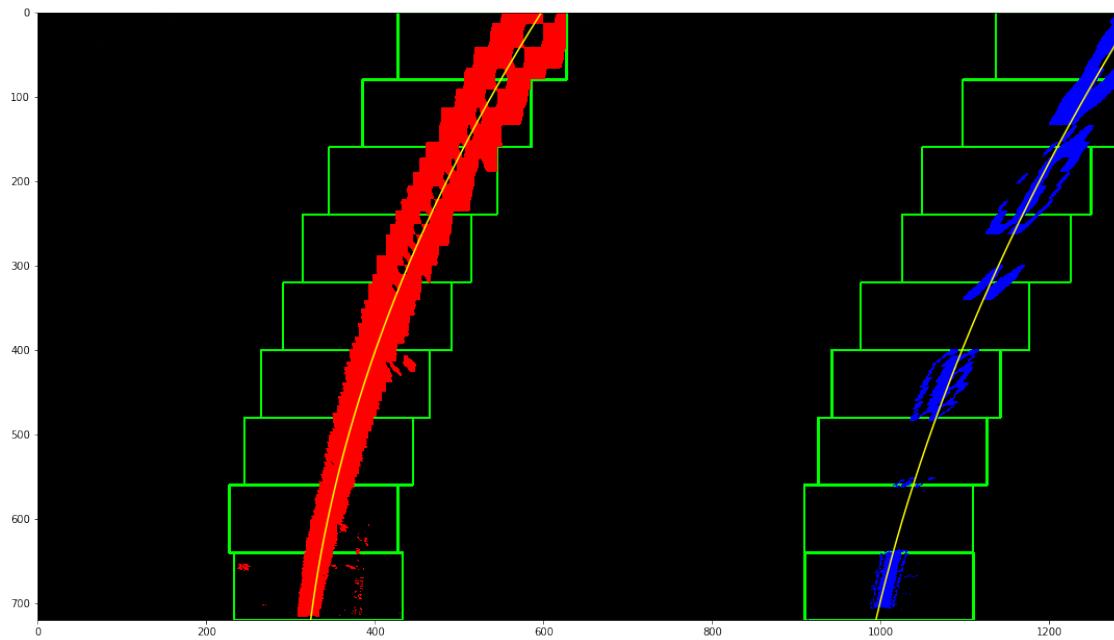
[38]: '\nf, ax = plt.subplots(1, 1, figsize=(24,
9))\nax.plot(histogram)\nplt.subplots_adjust(left=0., right=1, top=0.9,
bottom=0.)\n'

[39]: leftx, lefty, rightx, righty, out_img = aahlpf.find_lane_pixels(result_warped,
→h_frac=(3/4))

left_fit = np.polyfit(lefty, leftx, 2)
right_fit = np.polyfit(righty, rightx, 2)

left_xy, right_xy = aahlpf.fit_polynomial(result_warped, left_fit, right_fit)

```
[40]: f, ax = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax.imshow(out_img)
ax.plot(left_xy[0], left_xy[1], color='yellow')
ax.plot(right_xy[0], right_xy[1], color='yellow')
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



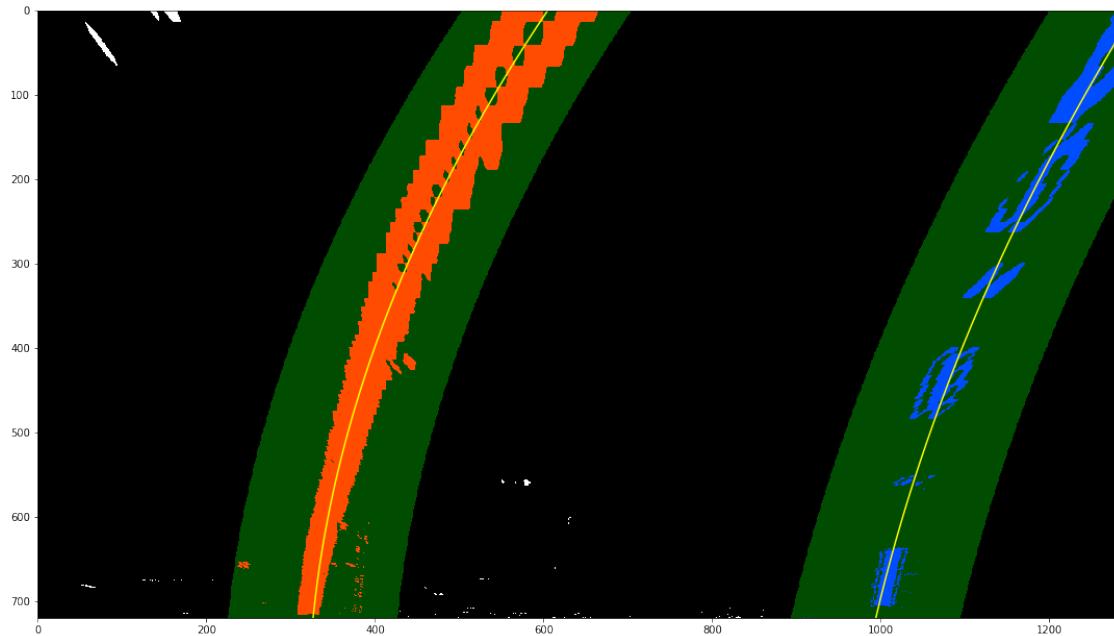
```
[41]: # f.savefig('output_images/test5_detect_lane_slide.jpg')
```

```
[42]: # Find our lane pixels first
leftx, lefty, rightx, righty, out_img = aahlpf.find_lane_pixels(result_warped,
                                                               h_frac=(3/4))

### TO-DO: Fit a second order polynomial to each using `np.polyfit` #####
left_fit = np.polyfit(lefty, leftx, 2)
right_fit = np.polyfit(righty, rightx, 2)

# Run image through the pipeline
# Note that in your project, you'll also want to feed in the previous fits
leftx, lefty, rightx, righty, out_img = aahlpf.
    →search_around_poly(result_warped, left_fit, right_fit)
left_fit = np.polyfit(lefty, leftx, 2)
right_fit = np.polyfit(righty, rightx, 2)
lane_pix_detect, left_xy, right_xy = aahlpf.visual_around_poly(result_warped,
                                                               left_fit, right_fit, out_img)
```

```
[43]: # View your output
f, ax = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax.imshow(lane_pix_detect)
plt.plot(left_xy[0], left_xy[1], color='yellow')
plt.plot(right_xy[0], right_xy[1], color='yellow')
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



```
[44]: # f.savefig('output_images/test5_detect_lane_prev.jpg')
```

```
[45]: leftx_conv, lefty_conv, rightx_conv, righty_conv, out_img_conv = aahlpf.
    →find_lane_pixels_conv(result_warped, h_frac=(3/4))

left_fit_conv = np.polyfit(lefty_conv, leftx_conv, 2)
right_fit_conv = np.polyfit(righty_conv, rightx_conv, 2)

left_xy_conv, right_xy_conv = aahlpf.fit_polynomial(result_warped, ↴
    →left_fit_conv, right_fit_conv)
```

```
[46]: '''
f, ax = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax.imshow(out_img_conv)
ax.plot(left_xy_conv[0], left_xy_conv[1], color='yellow')
ax.plot(right_xy_conv[0], right_xy_conv[1], color='yellow')
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
'''
```

```
[46]: "\nf, ax = plt.subplots(1, 1, figsize=(24,  
9))\nf.tight_layout()\nax.imshow(out_img_conv)\nax.plot(left_xy_conv[0],  
left_xy_conv[1], color='yellow')\nax.plot(right_xy_conv[0], right_xy_conv[1],  
color='yellow')\nplt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)\n"
```

0.7 Determine the curvature of the lane and vehicle position with respect to center

```
[47]: # Find our lane pixels first  
leftx, lefty, rightx, righty, out_img = aahlpf.find_lane_pixels(result_warped,  
→h_frac=(3/4))
```

```
### TO-DO: Fit a second order polynomial to each using `np.polyfit` ###  
left_fit = np.polyfit(lefty, leftx, 2)  
right_fit = np.polyfit(righty, rightx, 2)
```

```
# Generate x and y values for plotting  
ploty = np.linspace(0, result_warped.shape[0]-1, result_warped.shape[0] )
```

```
# Calculate the radius of curvature in pixels for both lane lines  
left_curverad, right_curverad = aahlpf.measure_curvature_pixels(ploty,  
→left_fit, right_fit)
```

```
[48]: # print(left_curverad, right_curverad)
```

```
[49]: y_eval = np.max(ploty)
```

```
left_fitx_eval = left_fit[0]*y_eval**2 + left_fit[1]*y_eval + left_fit[2]  
right_fitx_eval = right_fit[0]*y_eval**2 + right_fit[1]*y_eval + right_fit[2]
```

```
lane_center = np.abs(left_fitx_eval - right_fitx_eval)/2 + left_fitx_eval
```

```
vehicle_center = result_warped.shape[1]/2
```

```
vehicle_pos = vehicle_center - lane_center
```

```
[50]: # print('Vehicle Position: ', vehicle_pos)
```

```
[51]: # Find our lane pixels first
```

```
leftx, lefty, rightx, righty, out_img = aahlpf.find_lane_pixels(result_warped,  
→h_frac=(3/4))
```

```
ym_per_pix=(30/720)  
xm_per_pix=(3.7/700)
```

```
### TO-DO: Fit a second order polynomial to each using `np.polyfit` ###
```

```
left_fit_m = np.polyfit(ym_per_pix*lefty, xm_per_pix*leftx, 2)  
right_fit_m = np.polyfit(ym_per_pix*righty, xm_per_pix*rightx, 2)
```

```

# Generate x and y values for plotting
ploty = np.linspace(0, result_warped.shape[0]-1, result_warped.shape[0] )

# Calculate the radius of curvature in pixels for both lane lines
left_curverad_m, right_curverad_m = aahlpf.measure_curvature_real(ploty, ↴
    left_fit_m, right_fit_m)

[52]: # print(left_curverad_m, 'm', right_curverad_m, 'm')

[53]: print(left_curverad_m/right_curverad_m)
      print(right_curverad_m/left_curverad_m)

```

0.7687111808587435
1.3008786978782838

```

[54]: y_eval = np.max(ploty)
y_m = y_eval*ym_per_pix

left_fitx_eval_m = left_fit_m[0]*y_m**2 + left_fit_m[1]*y_m + left_fit_m[2]
right_fitx_eval_m = right_fit_m[0]*y_m**2 + right_fit_m[1]*y_m + right_fit_m[2]

lane_center_m = np.abs(left_fitx_eval_m - right_fitx_eval_m)/2 + ↴
    left_fitx_eval_m

vehicle_center_m = xm_per_pix*result_warped.shape[1]/2

vehicle_pos_m = vehicle_center_m - lane_center_m

[55]: # print('Vehicle Position (m): ', xm_per_pix*vehicle_pos)

[56]: lane_width_bottom = np.abs(left_fitx_eval - right_fitx_eval)
      print(lane_width_bottom)

```

670.5841996948775

```

[57]: y_min = np.min(ploty)

left_fitx_eval_min = left_fit[0]*y_min**2 + left_fit[1]*y_min + left_fit[2]
right_fitx_eval_min = right_fit[0]*y_min**2 + right_fit[1]*y_min + right_fit[2]

lane_width_top = np.abs(left_fitx_eval_min - right_fitx_eval_min)
print(lane_width_top)

```

704.1634075492692

```
[58]: print(np.abs(lane_width_bottom - lane_width_top))
```

33.57920785439171

```
[59]: print(left_fit)
      print(right_fit)
```

```
[ 3.48848130e-04 -6.31219280e-01  5.97240321e+02]
[ 2.68409537e-04 -6.20086585e-01  1.30140373e+03]
```

0.8 Warp the detected lane boundaries back onto the original image

```
[60]: # Create an image to draw the lines on
warp_zero = np.zeros_like(result_warped).astype(np.uint8)
color_warp = np.dstack((warp_zero, warp_zero, warp_zero))

# Recast the x and y points into usable format for cv2.fillPoly()
pts_left = np.array([np.transpose(np.vstack([left_xy[0], left_xy[1]]))])
pts_right = np.array([np.flipud(np.transpose(np.vstack([right_xy[0], right_xy[1]])))])
pts = np.hstack((pts_left, pts_right))

# Draw the lane onto the warped blank image
cv2.fillPoly(color_warp, np.int_(pts), (0,255, 0))

# Warp the blank back to original image space using inverse perspective matrix
# (Minv)
newwarp = cv2.warpPerspective(color_warp, Minv, (lane_undist.shape[1],
                                                 lane_undist.shape[0]))

# Combine the result with the original image
result_lane = cv2.addWeighted(lane_undist, 1, newwarp, 0.3, 0)
```

```
[61]: '''
f, ax = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax.imshow(result_lane)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
'''
```

```
[61]: '\nf, ax = plt.subplots(1, 1, figsize=(24,
9))\nf.tight_layout()\nax.imshow(result_lane)\nplt.subplots_adjust(left=0.,
right=1, top=0.9, bottom=0.)\n'
```

0.9 Output visual display of lane boundaries and lane curvature and vehicle position estimations

```
[62]: text1 = "Left Lane Curvature: " + str(left_curverad_m) + " m"
text2 = "Right Lane Curvature: " + str(right_curverad_m) + " m"
text3 = "Vehicle Position: " + str(xm_per_pix*vehicle_pos) + " m"
fontFace = cv2.FONT_HERSHEY_SIMPLEX
fontScale = 1.5;
thickness = 2;

img = np.copy(result_lane)

[63]: baseline=0;
textSize1, baseline1 = cv2.getTextSize(text1, fontFace, fontScale, thickness);
textSize2, baseline2 = cv2.getTextSize(text2, fontFace, fontScale, thickness);
textSize3, baseline3 = cv2.getTextSize(text3, fontFace, fontScale, thickness);

[64]: # center the text
textOrg1 = ((img.shape[1] - textSize1[0] - baseline1), (textSize1[1] + ↪baseline1))
textOrg2 = ((img.shape[1] - textSize2[0] - baseline2),
            (textSize1[1] + baseline1 + textSize2[1] + baseline2))
textOrg3 = ((img.shape[1] - textSize3[0] - baseline3),
            (textSize1[1] + baseline1 + textSize2[1] + baseline2 + textSize3[1] ↪+ baseline3))

[65]: # then put the text itself
cv2.putText(img, text1, textOrg1, fontFace, fontScale, (255, 255, 255), ↪thickness, 8);
cv2.putText(img, text2, textOrg2, fontFace, fontScale, (255, 255, 255), ↪thickness, 8);
cv2.putText(img, text3, textOrg3, fontFace, fontScale, (255, 255, 255), ↪thickness, 8);

[66]: f, ax = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax.imshow(img)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



```
[67]: # f.savefig('output_images/test5_curve_pos.jpg')
```

0.10 Process Video

```
[68]: # Import everything needed to edit/save/watch video clips
from moviepy.editor import VideoFileClip
from IPython.display import HTML
```

```
[69]: right_line = None
left_line = None
```

```
[70]: def process_image(image):
    # NOTE: The output you return should be a color image (3 channel) for
    # processing video below
    # TODO: put your pipeline here,
    # you should return the final output (image where lines are drawn on lanes)

    global left_line
    global right_line
    global M
    global Minv

    n = 3

    # Apply a distortion correction to raw images
    image_undist = cv2.undistort(image, mtx, dist, None, mtx)
```

```

# Use color transforms, gradients, etc., to create a thresholded binary
→image
binary_image = aahlpf.pipeline(image_undist)

# Apply a perspective transform to rectify binary image ("birds-eye view")
binary_warped = cv2.warpPerspective(binary_image, M, (binary_image.
→shape[1], binary_image.shape[0]),
                                    flags=cv2.INTER_LINEAR)

# Have lane lines been detected previously?
try:
    right_line
except NameError:
    right_line = None
    left_line = None

# print(right_line)
# print(left_line)

# Detect lane pixels and fit to find the lane boundary
if right_line is None:

    # Sliding window
    lefttx, lefty, rightx, righty, out_img = aahlpf.
→find_lane_pixels(binary_warped, h_frac=(3/4))
    left_fit = np.polyfit(lefty, lefttx, 2)
    right_fit = np.polyfit(righty, rightx, 2)
    left_xy, right_xy = aahlpf.fit_polynomial(binary_warped, left_fit,
→right_fit)

    # Save info about detected lane lines
    is_detected = True

    # Save info about detected lane lines
    ploty = np.linspace(0, binary_warped.shape[0]-1, binary_warped.shape[0])
    # Fit x values
    left_fitx_full = left_fit[0]*ploty**2 + left_fit[1]*ploty + left_fit[2]
    right_fitx_full = right_fit[0]*ploty**2 + right_fit[1]*ploty +
→right_fit[2]

else:

    # Search around polynomial
    lefttx, lefty, rightx, righty, out_img = aahlpf.search_around_poly(
        binary_warped, left_line.best_fit, right_line.best_fit)
    left_fit = np.polyfit(lefty, lefttx, 2)

```

```

right_fit = np.polyfit(righty, rightx, 2)

# Sanity check
# Find lane width
# Lane width at bottom of image
# Lane width at top of image
ploty = np.linspace(0, binary_warped.shape[0]-1, binary_warped.shape[0])
is_detected, lane_width, lane_width_min = aahlpf.sanity_check(
    ploty, left_fit, right_fit, leftx, lefty, rightx, righty,
    thresh_lane=(600, 800), thresh_lane_diff=200, thresh_curve=(7.0/4))

# Check fails
if not is_detected:

    # Sliding window
    leftx, lefty, rightx, righty, out_img = aahlpf.
    →find_lane_pixels(binary_warped, h_frac=(3/4))
    left_fit = np.polyfit(lefty, leftx, 2)
    right_fit = np.polyfit(righty, rightx, 2)

    # Sanity check
    # Find lane width
    # Lane width at bottom of image
    # Lane width at top of image
    ploty = np.linspace(0, binary_warped.shape[0]-1, binary_warped.shape[0])
    is_detected, lane_width, lane_width_min = aahlpf.sanity_check(
        ploty, left_fit, right_fit, leftx, lefty, rightx, righty,
        thresh_lane=(600, 800), thresh_lane_diff=200, thresh_curve=(7.0/4))

# Check doesn't fail
if is_detected:

    # Save info about detected lane lines
    #x values for detected line pixels
    right_line.allx.append(rightx)
    #y values for detected line pixels
    right_line.ally.append(righty)
    #x values for detected line pixels
    left_line.allx.append(leftx)
    #y values for detected line pixels
    left_line.ally.append(lefty)

    # Save info about detected lane lines
    ploty = np.linspace(0, binary_warped.shape[0]-1, binary_warped.
    →shape[0])
    # Fit x values

```

```

        left_fitx_full = left_fit[0]*ploty**2 + left_fit[1]*ploty + ↵
↳left_fit[2]
        right_fitx_full = right_fit[0]*ploty**2 + right_fit[1]*ploty + ↵
↳right_fit[2]

        # Save info about detected lane lines
        # x values of the last n fits of the line
        while(len(right_line.recent_xfitted) >= n):
            del right_line.recent_xfitted[0]
        right_line.recent_xfitted.append(right_fitx_full)
        # x values of the last n fits of the line
        while(len(left_line.recent_xfitted) >= n):
            del left_line.recent_xfitted[0]
        left_line.recent_xfitted.append(left_fitx_full)

        # Average results from previous frames
        leftx = []
        lefty = []
        rightx = []
        righty = []
        n_min = np.minimum(n, len(left_line.allx))

        # Average results from previous frames
        for i in range(n_min):
            leftx.append(left_line.allx[-1 - i])
            lefty.append(left_line.ally[-1 - i])
            rightx.append(right_line.allx[-1 - i])
            righty.append(right_line.ally[-1 - i])

        # Average results from previous frames
        leftx = np.concatenate(leftx)
        lefty = np.concatenate(lefty)
        rightx = np.concatenate(rightx)
        righty = np.concatenate(righty)

        # Average results from previous frames
        left_fit = np.polyfit(lefty, leftx, 2)
        right_fit = np.polyfit(righty, rightx, 2)
        left_xy, right_xy = aahlpf.fit_polynomial(binary_warped, left_fit, ↵
↳right_fit)

        # Save info about detected lane lines
        ploty = np.linspace(0, binary_warped.shape[0]-1, binary_warped.shape[0])
        # Fit x values
        left_fitx_full = left_fit[0]*ploty**2 + left_fit[1]*ploty + left_fit[2]
        right_fitx_full = right_fit[0]*ploty**2 + right_fit[1]*ploty + ↵
↳right_fit[2]

```

```

# Determine the curvature of the lane
ym_per_pix=(30/720)
xm_per_pix=(3.7/700)
left_fit_m = np.polyfit(ym_per_pix*lefty, xm_per_pix*leftx, 2)
right_fit_m = np.polyfit(ym_per_pix*righty, xm_per_pix*rightx, 2)
ploty = np.linspace(0, binary_warped.shape[0]-1, binary_warped.shape[0])
left_curverad_m, right_curverad_m = aahlpf.measure_curvature_real(ploty,✉
→left_fit_m, right_fit_m)

# Determine the vehicle position with respect to center
ploty = np.linspace(0, binary_warped.shape[0]-1, binary_warped.shape[0])
y_eval = np.max(ploty)
left_fitx_eval = left_fit[0]*y_eval**2 + left_fit[1]*y_eval + left_fit[2]
right_fitx_eval = right_fit[0]*y_eval**2 + right_fit[1]*y_eval +✉
→right_fit[2]
lane_center = np.abs(left_fitx_eval - right_fitx_eval)/2 + left_fitx_eval
vehicle_center = binary_warped.shape[1]/2
vehicle_pos = vehicle_center - lane_center
vehicle_pos_m = xm_per_pix*vehicle_pos

# Warp the detected lane boundaries back onto the original image
warp_zero = np.zeros_like(binary_warped).astype(np.uint8)
color_warp = np.dstack((warp_zero, warp_zero, warp_zero))
pts_left = np.array([np.transpose(np.vstack([left_xy[0], left_xy[1]]))])
pts_right = np.array([np.flipud(np.transpose(np.vstack([right_xy[0],✉
→right_xy[1])))])
pts = np.hstack((pts_left, pts_right))
cv2.fillPoly(color_warp, np.int_(pts), (0,255, 0))
newwarp = cv2.warpPerspective(color_warp, Minv, (image_undist.shape[1],✉
→image_undist.shape[0]))
image_lane_detect = cv2.addWeighted(image_undist, 1, newwarp, 0.3, 0)

# Output visual display of the lane boundaries and numerical estimation of✉
→lane curvature and vehicle position
text1 = "Left Lane Curvature: " + str(left_curverad_m) + "m"
text2 = "Right Lane Curvature: " + str(right_curverad_m) + "m"
text3 = "Vehicle Position: " + str(vehicle_pos_m) + "m"
fontFace = cv2.FONT_HERSHEY_SIMPLEX
fontScale = 1.5;
thickness = 2;
image_est = np.copy(image_lane_detect)
textSize1, baseline1 = cv2.getTextSize(text1, fontFace, fontScale,✉
→thickness);
textSize2, baseline2 = cv2.getTextSize(text2, fontFace, fontScale,✉
→thickness);

```

```

    textSize3, baseline3 = cv2.getTextSize(text3, fontFace, fontScale, □
→thickness);
    textOrg1 = ((image_est.shape[1] - textSize1[0] - baseline1), (textSize1[1] □
→+ baseline1))
    textOrg2 = ((image_est.shape[1] - textSize2[0] - baseline2),
                (textSize1[1] + baseline1 + textSize2[1] + baseline2))
    textOrg3 = ((image_est.shape[1] - textSize3[0] - baseline3),
                (textSize1[1] + baseline1 + textSize2[1] + baseline2 + □
→textSize3[1] + baseline3))
    cv2.putText(image_est, text1, textOrg1, fontFace, fontScale, (255, 255, □
→255), thickness, 8);
    cv2.putText(image_est, text2, textOrg2, fontFace, fontScale, (255, 255, □
→255), thickness, 8);
    cv2.putText(image_est, text3, textOrg3, fontFace, fontScale, (255, 255, □
→255), thickness, 8);

# Save info about detected lane lines
if right_line is None:

    right_line = aahlpf.Line()
    # was the line detected in the last iteration?
    right_line.detected = True
    # x values of the last n fits of the line
    right_line.recent_xfitted.append(right_fitx_full)
    #average x values of the fitted line over the last n iterations
    right_line.bestx = right_fitx_full
    #polynomial coefficients averaged over the last n iterations
    right_line.best_fit = right_fit
    #polynomial coefficients for the most recent fit
    right_line.current_fit = right_fit
    #radius of curvature of the line in meters
    right_line.radius_of_curvature = right_curverad_m
    #distance in meters of vehicle center from the line
    right_line.line_base_pos = vehicle_pos_m
    #difference in fit coefficients between last and new fits
    # right_line.diffs = np.array([0,0,0], dtype='float')
    #x values for detected line pixels
    right_line.allx = []
    right_line.allx.append(rightx)
    #y values for detected line pixels
    right_line.ally = []
    right_line.ally.append(righty)

    left_line = aahlpf.Line()
    # was the line detected in the last iteration?
    left_line.detected = True

```

```

# x values of the last n fits of the line
left_line.recent_xfitted.append(left_fitx_full)
#average x values of the fitted line over the last n iterations
left_line.bestx = left_fitx_full
#polynomial coefficients averaged over the last n iterations
left_line.best_fit = left_fit
#polynomial coefficients for the most recent fit
left_line.current_fit = left_fit
#radius of curvature of the line in meters
left_line.radius_of_curvature = left_curverad_m
#distance in meters of vehicle center from the line
left_line.line_base_pos = vehicle_pos_m
#difference in fit coefficients between last and new fits
left_line.diffs = np.array([0,0,0], dtype='float')
#x values for detected line pixels
left_line.allx = []
left_line.allx.append(leftx)
#y values for detected line pixels
left_line.ally = []
left_line.ally.append(lefty)

else:

    # was the line detected in the last iteration?
    right_line.detected = is_detected
    # x values of the last n fits of the line
    '''
    while(len(right_line.recent_xfitted) >= n):
        del right_line.recent_xfitted[0]
    right_line.recent_xfitted.append(right_fitx_full)
    '''
    #average x values of the fitted line over the last n iterations
    '''
    right_fitx_cat = np.vstack(right_line.recent_xfitted)
    right_fitx_ave = np.mean(right_fitx_cat, axis=0)
    right_line.bestx = right_fitx_ave
    '''

    right_line.bestx = right_fitx_full
    #polynomial coefficients averaged over the last n iterations
    right_line.best_fit = right_fit
    #polynomial coefficients for the most recent fit
    right_fit_last = right_line.current_fit
    right_line.current_fit = right_fit
    #radius of curvature of the line in meters
    right_line.radius_of_curvature = right_curverad_m
    #distance in meters of vehicle center from the line
    right_line.line_base_pos = vehicle_pos_m

```

```

#difference in fit coefficients between last and new fits
right_line.diffs = np.abs(right_fit_last - right_fit)
#x values for detected line pixels
# right_line.allx.append(rightx)
#y values for detected line pixels
# right_line.ally.append(righty)

# was the line detected in the last iteration?
left_line.detected = is_detected
# x values of the last n fits of the line
'''
while(len(left_line.recent_xfitted) >= n):
    del left_line.recent_xfitted[0]
left_line.recent_xfitted.append(left_fitx_full)
'''
#average x values of the fitted line over the last n iterations
'''
left_fitx_cat = np.vstack(left_line.recent_xfitted)
left_fitx_ave = np.mean(left_fitx_cat, axis=0)
left_line.bestx = left_fitx_ave
'''

left_line.bestx = left_fitx_full
#polynomial coefficients averaged over the last n iterations
left_line.best_fit = left_fit
#polynomial coefficients for the most recent fit
left_fit_last = left_line.current_fit
left_line.current_fit = left_fit
#radius of curvature of the line in meters
left_line.radius_of_curvature = left_curverad_m
#distance in meters of vehicle center from the line
left_line.line_base_pos = vehicle_pos_m
#difference in fit coefficients between last and new fits
left_line.diffs = np.abs(left_fit_last - left_fit)
#x values for detected line pixels
# left_line.allx.append(leftx)
#y values for detected line pixels
# left_line.ally.append(lefty)

return image_est

```

[71]: `print(len(lane_images))
print(lane_images)`

8

`['test_images\\straight_lines1.jpg', 'test_images\\straight_lines2.jpg',
'test_images\\test1.jpg', 'test_images\\test2.jpg', 'test_images\\test3.jpg',
'test_images\\test4.jpg', 'test_images\\test5.jpg', 'test_images\\test6.jpg']`

```
[72]: im_num = 5
print(lane_images[im_num])
lane_image = mpimg.imread(lane_images[im_num])
```

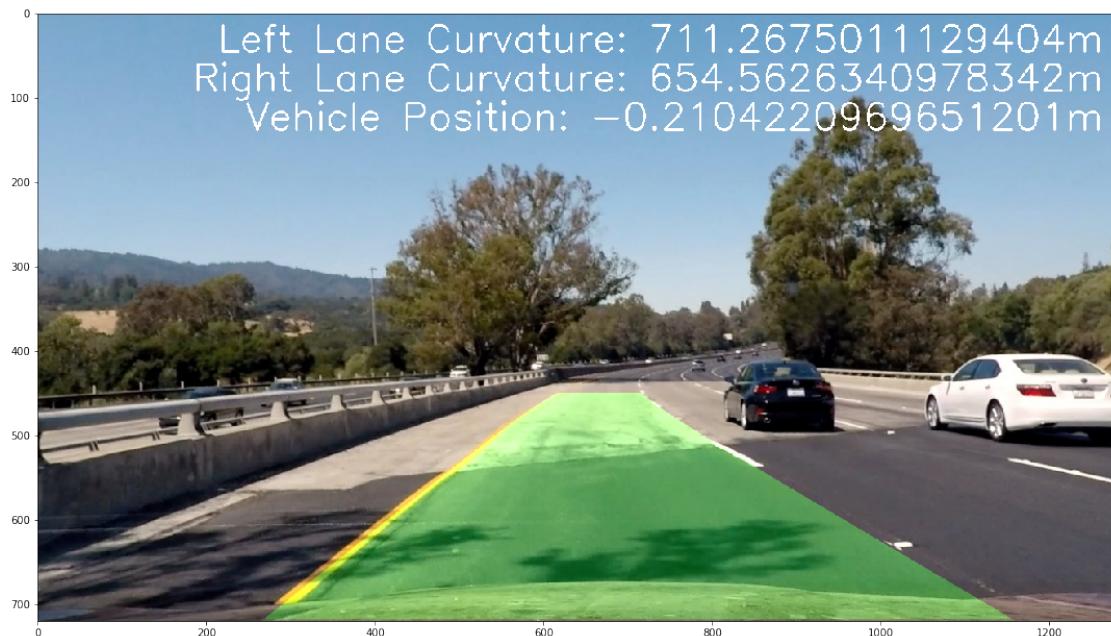
test_images\test4.jpg

```
[73]: test_output = process_image(lane_image)
```

```
[74]: print(len(left_line.recent_xfitted))
print(len(right_line.allx))
print(left_line.best_fit)
```

```
1
1
[ 2.30898644e-04 -3.00368386e-01  4.42493590e+02]
```

```
[75]: f, ax = plt.subplots(1, 1, figsize=(24, 9))
f.tight_layout()
ax.imshow(test_output)
plt.subplots_adjust(left=0., right=1, top=0.9, bottom=0.)
```



```
[77]: output = 'output_videos/project_video_out.mp4'
## To speed up the testing process you may want to try your pipeline on a
## shorter subclip of the video
## To do so add .subclip(start_second,end_second) to the end of the line below
```

```

## Where start_second and end_second are integer values representing the start
→and end of the subclip
## You may also uncomment the following line for a subclip of the first 5
→seconds
##clip1 = VideoFileClip("test_videos/solidWhiteRight.mp4").subclip(0,5)
clip1 = VideoFileClip("project_video.mp4")
clip = clip1.fl_image(process_image) #NOTE: this function expects color images!!
%time clip.write_videofile(output, audio=False)

```

Moviepy - Building video output_videos/project_video_out.mp4.

Moviepy - Writing video output_videos/project_video_out.mp4

```

t:  0%|
2/1260 [01:48<10:59,  1.91it/s, now=None]
t:  0%|
| 0/1260 [00:00<?, ?it/s, now=None]
t:  0%|
2/1260 [00:01<11:21,  1.84it/s, now=None]
t:  0%|
3/1260 [00:02<14:37,  1.43it/s, now=None]
t:  0%|
4/1260 [00:03<16:10,  1.29it/s, now=None]
t:  0%|
5/1260 [00:04<17:14,  1.21it/s, now=None]
t:  0%|
6/1260 [00:04<17:50,  1.17it/s, now=None]
t:  1%|
7/1260 [00:05<18:09,  1.15it/s, now=None]
t:  1%|
8/1260 [00:06<18:10,  1.15it/s, now=None]
t:  1%|
9/1260 [00:07<18:27,  1.13it/s, now=None]
t:  1%|
10/1260 [00:08<18:47,  1.11it/s, now=None]
t:  1%|
11/1260 [00:09<19:20,  1.08it/s, now=None]
t:  1%|
12/1260 [00:10<20:19,  1.02it/s, now=None]
t:  1%|
13/1260 [00:11<20:11,  1.03it/s, now=None]
t:  1%|
14/1260 [00:12<20:06,  1.03it/s, now=None]

```

t: 1%|
15/1260 [00:13<19:49, 1.05it/s, now=None]
t: 1%|
16/1260 [00:14<19:29, 1.06it/s, now=None]
t: 1%|
17/1260 [00:15<19:09, 1.08it/s, now=None]
t: 1%|
18/1260 [00:16<19:18, 1.07it/s, now=None]
t: 2%|
19/1260 [00:17<19:35, 1.06it/s, now=None]
t: 2%|
20/1260 [00:18<19:26, 1.06it/s, now=None]
t: 2%|
21/1260 [00:19<19:32, 1.06it/s, now=None]
t: 2%|
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991/1260 [18:06<04:29, 1.00s/it, now=None]
t: 79%|
992/1260 [18:07<04:20, 1.03it/s, now=None]
t: 79%|
993/1260 [18:07<04:11, 1.06it/s, now=None]
t: 79%|
994/1260 [18:08<04:12, 1.05it/s, now=None]
t: 79%|
995/1260 [18:09<04:17, 1.03it/s, now=None]
t: 79%|
996/1260 [18:11<04:27, 1.01s/it, now=None]
t: 79%|
997/1260 [18:12<04:38, 1.06s/it, now=None]
t: 79%|
998/1260 [18:13<04:35, 1.05s/it, now=None]

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t: 79%|          |
999/1260 [18:14<04:33,  1.05s/it, now=None]
t: 79%|          |
1000/1260 [18:15<04:21,  1.01s/it, now=None]
t: 79%|          |
1001/1260 [18:16<04:11,  1.03it/s, now=None]
t: 80%|          |
1002/1260 [18:16<03:49,  1.13it/s, now=None]
t: 80%|          |
1003/1260 [18:17<03:20,  1.28it/s, now=None]
t: 80%|          |
1004/1260 [18:17<03:00,  1.42it/s, now=None]
t: 80%|          |
1005/1260 [18:18<02:48,  1.52it/s, now=None]
t: 80%|          |
1006/1260 [18:18<02:37,  1.61it/s, now=None]
t: 80%|          |
1007/1260 [18:19<02:46,  1.52it/s, now=None]
t: 80%|          |
1008/1260 [18:20<02:46,  1.51it/s, now=None]
t: 80%|          |
1009/1260 [18:21<03:00,  1.39it/s, now=None]
t: 80%|          |
1010/1260 [18:22<03:09,  1.32it/s, now=None]
t: 80%|          |
1011/1260 [18:22<03:00,  1.38it/s, now=None]
t: 80%|          |
1012/1260 [18:23<02:54,  1.42it/s, now=None]
t: 80%|          |
1013/1260 [18:23<02:33,  1.61it/s, now=None]
t: 80%|          |
1014/1260 [18:24<02:18,  1.78it/s, now=None]
t: 81%|          |
1015/1260 [18:24<02:10,  1.88it/s, now=None]
t: 81%|          |
1016/1260 [18:25<02:05,  1.95it/s, now=None]
t: 81%|          |
1017/1260 [18:25<02:00,  2.01it/s, now=None]
t: 81%|          |
1018/1260 [18:26<01:59,  2.02it/s, now=None]
t: 81%|          |
1019/1260 [18:26<02:02,  1.97it/s, now=None]
t: 81%|          |
1020/1260 [18:27<02:04,  1.92it/s, now=None]
t: 81%|          |
1021/1260 [18:27<02:08,  1.86it/s, now=None]
t: 81%|          |
1022/1260 [18:28<02:18,  1.72it/s, now=None]
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t: 81%|           |
1023/1260 [18:29<02:22,  1.66it/s, now=None]
t: 81%|           |
1024/1260 [18:29<02:22,  1.65it/s, now=None]
t: 81%|           |
1025/1260 [18:30<02:26,  1.60it/s, now=None]
t: 81%|           |
1026/1260 [18:31<02:30,  1.55it/s, now=None]
t: 82%|           |
1027/1260 [18:31<02:26,  1.59it/s, now=None]
t: 82%|           |
1028/1260 [18:32<02:21,  1.64it/s, now=None]
t: 82%|           |
1029/1260 [18:32<02:20,  1.64it/s, now=None]
t: 82%|           |
1030/1260 [18:33<02:28,  1.55it/s, now=None]
t: 82%|           |
1031/1260 [18:34<02:34,  1.49it/s, now=None]
t: 82%|           |
1032/1260 [18:35<02:38,  1.44it/s, now=None]
t: 82%|           |
1033/1260 [18:35<02:46,  1.36it/s, now=None]
t: 82%|           |
1034/1260 [18:36<02:46,  1.36it/s, now=None]
t: 82%|           |
1035/1260 [18:37<02:53,  1.30it/s, now=None]
t: 82%|           |
1036/1260 [18:38<02:59,  1.25it/s, now=None]
t: 82%|           |
1037/1260 [18:39<03:04,  1.21it/s, now=None]
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1038/1260 [18:40<03:16,  1.13it/s, now=None]
t: 82%|           |
1039/1260 [18:41<03:25,  1.07it/s, now=None]
t: 83%|           |
1040/1260 [18:42<03:45,  1.02s/it, now=None]
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1043/1260 [18:45<04:01,  1.11s/it, now=None]
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1044/1260 [18:47<04:00,  1.11s/it, now=None]
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1046/1260 [18:49<03:55,  1.10s/it, now=None]
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1047/1260 [18:50<03:52, 1.09s/it, now=None]
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1048/1260 [18:51<03:57, 1.12s/it, now=None]
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1049/1260 [18:52<03:54, 1.11s/it, now=None]
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1051/1260 [18:54<03:44, 1.07s/it, now=None]
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1057/1260 [19:01<03:45, 1.11s/it, now=None]
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1058/1260 [19:02<03:42, 1.10s/it, now=None]
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1059/1260 [19:03<03:44, 1.12s/it, now=None]
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1061/1260 [19:06<03:57, 1.19s/it, now=None]
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1063/1260 [19:08<03:55, 1.19s/it, now=None]
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1064/1260 [19:09<03:54, 1.20s/it, now=None]
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1069/1260 [19:14<03:27, 1.09s/it, now=None]
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1071/1260 [19:17<03:30, 1.11s/it, now=None]
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1072/1260 [19:18<03:27, 1.11s/it, now=None]
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1073/1260 [19:19<03:27, 1.11s/it, now=None]
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1074/1260 [19:20<03:24, 1.10s/it, now=None]
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1079/1260 [19:25<03:17, 1.09s/it, now=None]
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1080/1260 [19:27<03:19, 1.11s/it, now=None]
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1081/1260 [19:28<03:15, 1.09s/it, now=None]
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1083/1260 [19:30<03:14, 1.10s/it, now=None]
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1084/1260 [19:31<03:12, 1.09s/it, now=None]
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1086/1260 [19:33<03:09, 1.09s/it, now=None]
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1087/1260 [19:34<03:05, 1.07s/it, now=None]
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1088/1260 [19:35<03:02, 1.06s/it, now=None]
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1089/1260 [19:36<03:02, 1.06s/it, now=None]
t: 87%| |
1090/1260 [19:37<03:02, 1.07s/it, now=None]
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1091/1260 [19:38<03:03, 1.08s/it, now=None]
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1092/1260 [19:40<03:06, 1.11s/it, now=None]
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1093/1260 [19:41<03:07, 1.12s/it, now=None]
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t: 87%| |
1095/1260 [19:43<03:05, 1.12s/it, now=None]
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1096/1260 [19:44<03:02, 1.12s/it, now=None]
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1097/1260 [19:45<03:00, 1.11s/it, now=None]
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1098/1260 [19:46<03:00, 1.11s/it, now=None]
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1099/1260 [19:47<02:58, 1.11s/it, now=None]
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1101/1260 [19:50<02:54, 1.10s/it, now=None]
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1102/1260 [19:51<02:57, 1.12s/it, now=None]
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1103/1260 [19:52<02:58, 1.13s/it, now=None]
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1106/1260 [19:56<02:58, 1.16s/it, now=None]
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1107/1260 [19:57<03:02, 1.19s/it, now=None]
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1108/1260 [19:58<03:02, 1.20s/it, now=None]
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1109/1260 [19:59<02:59, 1.19s/it, now=None]
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1110/1260 [20:00<02:57, 1.18s/it, now=None]
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1111/1260 [20:02<02:56, 1.19s/it, now=None]
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1112/1260 [20:03<02:52, 1.17s/it, now=None]
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1113/1260 [20:04<02:49, 1.15s/it, now=None]
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1114/1260 [20:05<02:48, 1.15s/it, now=None]
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1115/1260 [20:06<02:49, 1.17s/it, now=None]
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1116/1260 [20:07<02:47, 1.17s/it, now=None]
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1117/1260 [20:08<02:45, 1.16s/it, now=None]
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1118/1260 [20:10<02:41, 1.14s/it, now=None]

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t: 89%|      |
1119/1260 [20:11<02:37,  1.12s/it, now=None]
t: 89%|      |
1120/1260 [20:12<02:34,  1.11s/it, now=None]
t: 89%|      |
1121/1260 [20:13<02:33,  1.11s/it, now=None]
t: 89%|      |
1122/1260 [20:14<02:35,  1.13s/it, now=None]
t: 89%|      |
1123/1260 [20:15<02:33,  1.12s/it, now=None]
t: 89%|      |
1124/1260 [20:16<02:31,  1.12s/it, now=None]
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1125/1260 [20:17<02:32,  1.13s/it, now=None]
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1126/1260 [20:19<02:33,  1.15s/it, now=None]
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1127/1260 [20:20<02:34,  1.16s/it, now=None]
t: 90%|      |
1128/1260 [20:21<02:34,  1.17s/it, now=None]
t: 90%|      |
1129/1260 [20:22<02:35,  1.19s/it, now=None]
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1130/1260 [20:23<02:34,  1.19s/it, now=None]
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1131/1260 [20:24<02:31,  1.18s/it, now=None]
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1132/1260 [20:26<02:30,  1.18s/it, now=None]
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1133/1260 [20:27<02:27,  1.16s/it, now=None]
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1134/1260 [20:28<02:26,  1.16s/it, now=None]
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1135/1260 [20:29<02:27,  1.18s/it, now=None]
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1136/1260 [20:30<02:24,  1.17s/it, now=None]
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1137/1260 [20:31<02:22,  1.16s/it, now=None]
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1138/1260 [20:33<02:21,  1.16s/it, now=None]
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1139/1260 [20:34<02:18,  1.15s/it, now=None]
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1140/1260 [20:35<02:16,  1.14s/it, now=None]
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1141/1260 [20:36<02:14,  1.13s/it, now=None]
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1142/1260 [20:37<02:12,  1.12s/it, now=None]
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t: 91%| |
1143/1260 [20:38<02:11, 1.12s/it, now=None]
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1144/1260 [20:39<02:09, 1.12s/it, now=None]
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1145/1260 [20:40<02:08, 1.12s/it, now=None]
t: 91%| |
1146/1260 [20:42<02:07, 1.12s/it, now=None]
t: 91%| |
1147/1260 [20:43<02:07, 1.13s/it, now=None]
t: 91%| |
1148/1260 [20:44<02:04, 1.12s/it, now=None]
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1149/1260 [20:45<02:04, 1.12s/it, now=None]
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1150/1260 [20:46<02:03, 1.13s/it, now=None]
t: 91%| |
1151/1260 [20:47<02:02, 1.12s/it, now=None]
t: 91%| |
1152/1260 [20:48<02:01, 1.12s/it, now=None]
t: 92%| |
1153/1260 [20:49<02:00, 1.13s/it, now=None]
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1154/1260 [20:51<02:00, 1.14s/it, now=None]
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1155/1260 [20:52<02:00, 1.15s/it, now=None]
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1156/1260 [20:53<02:00, 1.15s/it, now=None]
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1157/1260 [20:54<01:57, 1.15s/it, now=None]
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1158/1260 [20:55<01:58, 1.16s/it, now=None]
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1159/1260 [20:56<01:59, 1.18s/it, now=None]
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1160/1260 [20:58<01:56, 1.17s/it, now=None]
t: 92%| |
1161/1260 [20:59<01:54, 1.15s/it, now=None]
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1162/1260 [21:00<01:51, 1.14s/it, now=None]
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1163/1260 [21:01<01:48, 1.12s/it, now=None]
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1164/1260 [21:02<01:47, 1.12s/it, now=None]
t: 92%| |
1165/1260 [21:03<01:45, 1.11s/it, now=None]
t: 93%| |
1166/1260 [21:04<01:43, 1.10s/it, now=None]

t: 93%| |
1167/1260 [21:05<01:41, 1.09s/it, now=None]
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1172/1260 [21:10<01:33, 1.06s/it, now=None]
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1173/1260 [21:12<01:32, 1.07s/it, now=None]
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1174/1260 [21:13<01:31, 1.06s/it, now=None]
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1175/1260 [21:14<01:29, 1.05s/it, now=None]
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1178/1260 [21:17<01:26, 1.05s/it, now=None]
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1179/1260 [21:18<01:24, 1.04s/it, now=None]
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1180/1260 [21:19<01:22, 1.04s/it, now=None]
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1181/1260 [21:20<01:21, 1.04s/it, now=None]
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1183/1260 [21:22<01:20, 1.04s/it, now=None]
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1184/1260 [21:23<01:18, 1.04s/it, now=None]
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1185/1260 [21:24<01:18, 1.05s/it, now=None]
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1186/1260 [21:25<01:17, 1.05s/it, now=None]
t: 94%| |
1187/1260 [21:26<01:16, 1.05s/it, now=None]
t: 94%| |
1188/1260 [21:27<01:15, 1.04s/it, now=None]
t: 94%| |
1189/1260 [21:28<01:13, 1.04s/it, now=None]
t: 94%| |
1190/1260 [21:29<01:13, 1.05s/it, now=None]

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t: 95%| |
1191/1260 [21:30<01:12, 1.05s/it, now=None]
t: 95%| |
1192/1260 [21:31<01:12, 1.07s/it, now=None]
t: 95%| |
1193/1260 [21:33<01:12, 1.08s/it, now=None]
t: 95%| |
1194/1260 [21:34<01:10, 1.07s/it, now=None]
t: 95%| |
1195/1260 [21:35<01:09, 1.07s/it, now=None]
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1196/1260 [21:36<01:09, 1.08s/it, now=None]
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1197/1260 [21:37<01:08, 1.09s/it, now=None]
t: 95%| |
1198/1260 [21:38<01:07, 1.08s/it, now=None]
t: 95%| |
1199/1260 [21:39<01:04, 1.06s/it, now=None]
t: 95%| |
1200/1260 [21:40<01:03, 1.05s/it, now=None]
t: 95%| |
1201/1260 [21:41<01:02, 1.05s/it, now=None]
t: 95%| |
1202/1260 [21:42<01:01, 1.06s/it, now=None]
t: 95%| |
1203/1260 [21:43<01:00, 1.06s/it, now=None]
t: 96%| |
1204/1260 [21:44<00:58, 1.05s/it, now=None]
t: 96%| |
1205/1260 [21:45<00:57, 1.04s/it, now=None]
t: 96%| |
1206/1260 [21:46<00:55, 1.04s/it, now=None]
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1207/1260 [21:47<00:55, 1.04s/it, now=None]
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1208/1260 [21:48<00:55, 1.06s/it, now=None]
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1209/1260 [21:49<00:54, 1.06s/it, now=None]
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1211/1260 [21:52<00:53, 1.09s/it, now=None]
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1212/1260 [21:53<00:51, 1.08s/it, now=None]
t: 96%| |
1213/1260 [21:54<00:50, 1.07s/it, now=None]
t: 96%| |
1214/1260 [21:55<00:47, 1.04s/it, now=None]
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t: 96%| |
1215/1260 [21:56<00:45, 1.02s/it, now=None]
t: 97%| |
1216/1260 [21:57<00:47, 1.07s/it, now=None]
t: 97%| |
1217/1260 [21:58<00:45, 1.06s/it, now=None]
t: 97%| |
1218/1260 [21:59<00:44, 1.05s/it, now=None]
t: 97%| |
1219/1260 [22:00<00:42, 1.03s/it, now=None]
t: 97%| |
1220/1260 [22:01<00:40, 1.02s/it, now=None]
t: 97%| |
1221/1260 [22:02<00:39, 1.02s/it, now=None]
t: 97%| |
1222/1260 [22:03<00:38, 1.01s/it, now=None]
t: 97%| |
1223/1260 [22:04<00:37, 1.02s/it, now=None]
t: 97%| |
1224/1260 [22:05<00:36, 1.02s/it, now=None]
t: 97%| |
1225/1260 [22:06<00:35, 1.02s/it, now=None]
t: 97%| |
1226/1260 [22:07<00:34, 1.03s/it, now=None]
t: 97%| |
1227/1260 [22:08<00:33, 1.03s/it, now=None]
t: 97%| |
1228/1260 [22:09<00:32, 1.02s/it, now=None]
t: 98%| |
1229/1260 [22:10<00:31, 1.02s/it, now=None]
t: 98%| |
1230/1260 [22:11<00:30, 1.01s/it, now=None]
t: 98%| |
1231/1260 [22:12<00:29, 1.01s/it, now=None]
t: 98%| |
1232/1260 [22:13<00:28, 1.01s/it, now=None]
t: 98%| |
1233/1260 [22:14<00:27, 1.02s/it, now=None]
t: 98%| |
1234/1260 [22:15<00:26, 1.03s/it, now=None]
t: 98%| |
1235/1260 [22:16<00:25, 1.04s/it, now=None]
t: 98%| |
1236/1260 [22:17<00:25, 1.04s/it, now=None]
t: 98%| |
1237/1260 [22:18<00:24, 1.05s/it, now=None]
t: 98%| |
1238/1260 [22:19<00:22, 1.04s/it, now=None]
```

```
t: 98%| |
1239/1260 [22:21<00:22, 1.05s/it, now=None]
t: 98%| |
1240/1260 [22:22<00:21, 1.05s/it, now=None]
t: 98%| |
1241/1260 [22:23<00:20, 1.07s/it, now=None]
t: 99%| |
1242/1260 [22:24<00:19, 1.08s/it, now=None]
t: 99%| |
1243/1260 [22:25<00:18, 1.09s/it, now=None]
t: 99%||
1244/1260 [22:26<00:17, 1.11s/it, now=None]
t: 99%||
1245/1260 [22:27<00:16, 1.12s/it, now=None]
t: 99%||
1246/1260 [22:28<00:15, 1.13s/it, now=None]
t: 99%||
1247/1260 [22:30<00:14, 1.15s/it, now=None]
t: 99%||
1248/1260 [22:31<00:13, 1.16s/it, now=None]
t: 99%||
1249/1260 [22:32<00:12, 1.17s/it, now=None]
t: 99%||
1250/1260 [22:33<00:11, 1.16s/it, now=None]
t: 99%||
1251/1260 [22:34<00:10, 1.15s/it, now=None]
t: 99%||
1252/1260 [22:35<00:09, 1.15s/it, now=None]
t: 99%||
1253/1260 [22:37<00:08, 1.15s/it, now=None]
t: 100%||
1254/1260 [22:38<00:06, 1.14s/it, now=None]
t: 100%||
1255/1260 [22:39<00:05, 1.13s/it, now=None]
t: 100%||
1256/1260 [22:40<00:04, 1.14s/it, now=None]
t: 100%||
1257/1260 [22:41<00:03, 1.15s/it, now=None]
t: 100%||
1258/1260 [22:42<00:02, 1.17s/it, now=None]
t: 100%||
1259/1260 [22:44<00:01, 1.18s/it, now=None]
t: 100%||
1260/1260 [22:45<00:00, 1.17s/it, now=None]
```

Moviepy - Done !

```
Moviepy - video ready output_videos/project_video_out.mp4
```

```
t: 0%|
```

```
Wall time: 22min 47s
```

```
[78]: HTML("""  
    <video width="960" height="540" controls>  
        <source src="{0}">  
    </video>  
""").format(output))
```

```
[78]: <IPython.core.display.HTML object>
```