**Capstone: State Farm Distracted Driver Detection**

Natraj Rajput January 17, 2018

1. **Definition**
   1. **Project Overview**

The domain of this problem is computer vision. Computer vision is a branch of machine learning concerned with the automatic extraction, analysis and understanding of useful information from a single image or a sequence of images (BMVA, n.d.). Computer vision began in the 1960’s, when a person named Larry Roberts wrote his PhD thesis on the possibility of extracting 3D details and information from 2D images(T.S. Huang, n.d.). In the 70’s, some progress was made on the interpretation of 2d images to 3d images (Hari Narayanan, et al, n.d.). In the 80’s, optical character recognition systems that recognize letters, symbols and numbers were used in several industries (Quick history, n.d.). In the 90’s, new applications of computer vision were possible as computers became more powerful and common (Quick history, n.d.). In the 2000’s, computer vision was used to process large datasets, videos and could understand motion, patterns and predict outcomes (Hari Narayanan, et al, n.d.). The [dataset](file:///C:\Users\ndrs\AppData\Roaming\Microsoft\Word\State%20Farm%20Distracted%20Driver%20Dataset.%20(2016).%20In%20Kaggle.%20Retrieved%20October%2025,%202017,%20from%20https:\www.kaggle.com\c\state-farm-distracted-driver-detection\data) being considered is the one provided in the Kaggle competition. It contains 2 folders, one with the training images and the other with the test images. The images capture the driver from a side-view dashboard camera. An excel file has also been provided and it links the images with its respective drivers for only the Train dataset.

* 1. **Problem Statement**

The problem that we are trying to solve is a multi-class classification problem. We are tasked to properly predict and classify driver’s behavior given the dashboard images of people doing 10 different actions, 9 of which are considered actions of distracted behavior. The 10 classes are as follows: c0: safe driving, c1: texting – right, c2: talking on the phone – right, c3: texting – left, c4: talking on the phone – left, c5: operating the radio, c6: drinking, c7: reaching behind, c8: hair and makeup, c9: talking to passenger.

A solution to this problem is using machine learning computer vision models to classify driver actions. Working with Convolutional Neural Networks would be a good idea because CNN’s are known to yield the most accurate results in the computer vision field. Keras application models with pre-trained weights could reduce the time it takes to train while still maintaining good results. Reducing image size and dividing the images into the RGB channels could make processing of the images more manageable. Pre-processing the images may be necessary to reduce overfitting and improve generalization. Once the model is fit, we will need to predict the labels of the test set to determine which of 10 categories each picture belongs to. The validation results and benchmark result will then tell us if we still need to improve the model. We are trying to achieve a log loss that would be closest to zero and should at least be within the top 10% of the Kaggle public leaderboard.

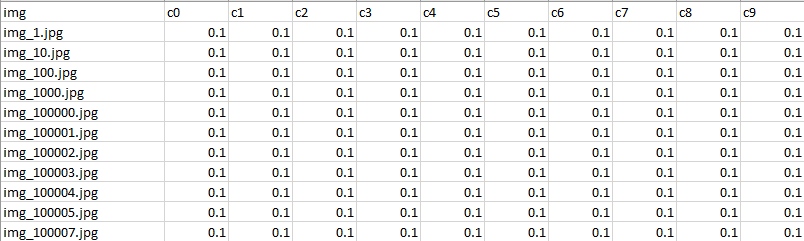
An outlined solution is, Step 1, import the training data. Step 2, split the training data into 2 subsets, a train subset and a validation subset. Step 3, Reduce and scale images from the dataset to a more manageable size. Step 4, augment the dataset by adding images with noise. Step 5, make the CNN architecture but most optimally make use of the keras application and pre-trained model weights such as Xception, VGG-16, Resnet50. Step 6, fit the model and save the resulted weights. Step 7, test using the validation subset. Step 8, validate results/accuracy. Step 9, Plot the train and test dataset against the fitted values/epoch to see how much the model is overfitting. Step 10, Predict the labels of the test dataset then submit it to Kaggle. Step 11, compare Kaggle result to see if it meets benchmark results. Step 11, Adjust architecture, model, parameters and data augmentation. Step 12, Repeat until it meets target benchmark results. Step 13, make final adjustments.

* 1. **Metrics**

I will make use of the Multi-class logarithmic loss. This metric is used in many computer vision classification problems because it measures the accuracy of a classifier by penalizing false classifications. It is also a good metric for this problem because in order to calculate log-loss, the classifier must assign a probability to each class rather than yielding the most likely class. Having a good log loss would mean we are generalizing all categories well and not only favoring and generalizing few categories. Since we also need to compare our results to a benchmark, it would be best to stick with the metric made use in the Kaggle competition.

-log P(yt|yp) = -(yt log(yp) + (1 - yt) log(1 - yp))

Sample output:



Multi class log loss example:

**>**LogLossMulti (["bam", "ham", "spam"], [[1, 0, 0], [0, 1, 0], [0, 0, 1]])

[1] 2.1094237467877998e-15

**>**LogLossMulti (["bam", "ham", "spam"], [[0, 0, 1], [1, 0, 0], [0, 1, 0]])

[1] 34.538776394910684

**>**LogLossMulti (["bam", "ham", "spam", "spam"], [[0.8, 0.1, 0.1], [0.3, 0.6, 0.1], [0.15, 0.15, 0.7], [0.05, 0.05, 0.9]])

[1] 0.2990

***Retrieved from Mark Needham,first steps with log loss***<http://www.markhneedham.com/blog/2016/09/14/scikit-learn-first-steps-with-log_loss/>

From this example, we can see that when the prediction is completely the same as the actual value, the log loss results to a 2.11e-15 and when the prediction is completely wrong, the log loss reaches 34.54.

1. **Analysis(2-4 pages)**
   1. **Data Exploration**

There are a total of 22424 images in the train dataset and 79726 images for the test dataset. All images are colored and 640 x 480 pixels in size. The images capture the driver from a side-view dashboard camera. The provided test dataset has no information as to what classification the pictures belong to and as such can be considered unseen data.

2489,2267,2317,2346,2326,2312,2325,2002,1911,2129

Sample image:



* 1. **Exploratory Visualization**
  2. **Algorithms and Techniques**

The main model architecture that will be used is a Keras Application Model. These architectures have been perfected to classify images. Keras also has the option of making use of pretrained weights based of **ImageNet**. Making use of these pretrained weights can drastically reduce the time it will take to train and optimize the model.

The algorithms and techniques I intend to use and update are:

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* + 1. Keras Application Models
       1. Model -This is the main architecture that will be used to train our images. Architectures that I will try are VGG16, VGG19, ResNet50, Xception, Inceptionv3, InceptionResNetv2, MobileNet
       2. Weights- Random initialization or pretrained on ‘ImageNet’
    2. Neural Network Architecture
       1. Number of layers
       2. Layer types – Include Core, Pooling, Convolutional, Normalization and Noise layers
       3. Layer Parameters
    3. Preprocessing Parameters (see the Data Preprocessing section)
    4. Training Parameters
       1. Epochs- Training length
       2. Batch size- Number of tensors/images to be trained per epoch.
       3. Activation- The optimization algorithm to use for learning. Activation functions include softmax, elu, selu, softplus,softsign, relu, tanh, sigmoid, hard sigmoid and linear.
       4. Learning Rate- The learning speed of the algorithm
       5. Weight Decay- Regularization method used to prevent weights from growing too large
       6. Momentum- Technique used for accelerating gradient descent by making use of accumulated velocity.
    5. Callbacks
       1. Early Stopping- Technique used to reduce the training time when validation loss is not decreasing anymore.
       2. Model Checkpoint- Technique used for saving important weights.
    6. Cross Validation Techniques
       1. Kfold cross validation – technique used to train and evaluate models by randomly partitioning original samples into k equal sized subsamples. Each subsample is divided into a train and validation dataset.
    7. Other techniques
       1. Mean/Averaging Predictions- technique used to improve generalization by averaging out multiple predictions.

* 1. **Benchmark**

The benchmark result will be based on the Kaggle public leaderboard as I was unable to find a benchmark model as such. Since everyone in the leaderboard must follow the same rules and evaluation metric, it makes it good for benchmarking. My target result for this project is to reach the top 10% (≤ 144 of 1440) people with a logloss ≤ 0.24859. The target result is based on the log loss value of the predicted labels against the actual labels of the 79726 test images.

1. **Methodology(3-5 pages)**
   1. **Data Preprocessing**

The data preprocessing done are as follows:

1. Images are converted into 3 channels, RGB – This preprocessing is done so models may use the 3 channels to learn features with the objective of improving accuracy and log loss.
2. Images are resized to 224 x 224 – Resizing images makes it easier to load on memory at the cost of losing some details.
3. Image labels are converted to categorical integer features/vectors – This is done using the one-hot scheme. This encoding is needed for feeding categorical data to our models because it is the most practical way for models to read categorical data.
4. The list of Images is shuffled– Randomizing images is simply done to change the default order.
5. The list of images are divided into a train set and validation set - This division is important so that we could validate if our model is improving or not when it is training.
6. Pixel values are converted to 32 bit floats – This is done so we could rescale our images
7. Pixel values are divided by 255 – We divide our data by 255 because it is the maximum RGB value and we want our data to be within the range of 0 and 1.
8. Some images are randomly augmented using the following:
   * + 1. Random – Adding a touch of chance is known to improve accuracy and reduce overfitting in deep learning. This can be seen in everything from random weight initializations of models to dropout layers.
       2. Augmentations - Since not all dashboard images are taken in exactly the same spot, these augmentations provide a means of improving generalization.
          1. Zoom
          2. Width Shift
          3. Height Shift
          4. Rotation

Sample Output:

* 1. **Implementation**

This first implementation followed the steps as outlined in the problem statement and the solution is as follows:

1. Import data
   * + 1. Implementation: Created a function that would read all images. One function for reading the train dataset and another function for reading the test dataset
       2. Complications: It is a time-consuming and memory expensive process.
2. Split train dataset into train and validation subsets
   * + 1. Implementation: Split the dataset using train\_test\_split function of sklearn.
3. Preprocess dataset
   * + 1. Implementation: Data preprocessing is done as explained in the previous section
       2. Complications: The data preprocessing is memory expensive
4. Create Model Architecture
   * + 1. Implementation: Used the Keras application models then to finalize, I added my own layers with default parameters.
5. Train model
   * + 1. Implementation: Used Keras fit function to train the model.
6. Test model
   * + 1. Implementation: Used the validation set to test the model locally. Then when I was satisfied, I tested the model on the test dataset and submitted to Kaggle to see final results.
       2. Complications: loading the whole test dataset was memory expensive
   1. **Refinement**

Please refer to \_\_\_\_\_ notebook for my initial solution.

Please Refer to \_\_\_\_\_ notebook for my second solution

Please Refer to \_\_\_\_\_ notebook for my final solution

The first solution as seen in the previous section was a solution that left all parameters in its default state. Parameters that had no default state were selected at random. This solution was simply created to get things started and begin the refinement process. The log loss this implementation achieved in the whole test dataset is 7.541.

The second solution had reached its peak performance and could not be further improved despite weeks of research, refinements, trial and error. The lowest log loss that it achieved on the whole test dataset is 0.815. The model does well but it was still not enough to beat the benchmark result of 0.248. The refinements done on the first solution to come up with this solution is as follows:

1. Implemented a function that would save read data into cache files.
2. Made a function that would split the train dataset into 3(train, validation and test), this is so my local test would yield a similar log loss to the actual test dataset.
3. Train, validation and test sets are saved in different cache files to reduce memory usage.
4. Data Augmentations and parameters were based on logic, log loss and the train vs validation plot
5. Selected the application model and weight initialization that resulted to the best log loss
6. Selected the layers and layer types and layer parameters that yield the best results
7. Selected the best activation based on the problem and trial and error
8. Selected the most effective optimizer based on its default parameters.
9. Learning rate, weight decay and momentum were selected and updated based on the train vs validation plot
10. Batch size was selected based on GPU memory capabilities
11. Epochs was selected based on the log loss improvement
12. Created a function that splits the test dataset into 5. This is done to reduce the memory usage.

For this final solution, most parameters mentioned in the previous solution had to be tweaked after adding the new refinements. This is due to the better understanding of the problem that was yielding poor results and after months’ worth of iterations, trial and error. To get the final solution, these are the new refinements that were done:

1. Applied the K-fold cross validation technique to maximize the learning of train dataset.
2. Used the Mean/Averaging predictions technique to make predictions. This is used to improve the generalization capabilities by averaging the prediction results of the model with different weights created from using the K-fold cross validation technique.
3. The next refinement was the adding of the Early stopping technique. This technique reduces the time it takes to train when there are no notable validation loss improvements.
4. One other technique was sorting out the images by the drivers to reduce counter overfitting. It appears that the model was overfitting and memorizing the drivers so when exposed to new drivers it would not do as well.
5. Made use of batch normalization technique to provide the final layer of the neural network an input that has zero mean and standard deviation close to one. This is done to train the network faster and generally improve the accuracy.
6. **Results(2-3 pages)**
   1. **Model Evaluation and Validation**

The final model architecture and parameters were selected based on the validation loss and test results. Multiple tests and refinements had to be done on the model and parameters before I could achieve optimal results.

The model architecture and parameters are as follows:

* + 1. The model input uses the default shape of our keras application model. The shape is 224, 224, 3.
    2. The Keras application model I used and selected is ResNet50. This decision was entirely based on the validation results. I tried and tested all Keras application models from VGG16 to MobileNet.
    3. Made use of the ‘ImageNet’ (pre-trained) weights for the Keras application model because the random initializations option did not provide results anywhere near that of ‘ImageNet’. Also using pre-trained weights option is known to yield decent results when working on similar classification problems without needing to spend too much time training the model.
    4. The output of the Keras application model is then applied a Global Max Pooling 2D layer because it used to reduce the dimensionality of the data and partly reduce overfitting. Using a Global Average Pooling 2d does only slightly worse and not using either would significantly (negatively) affect the end results.
    5. Applied a dense layer with 512 units. This is done to change the dimensionality of the vectors and is basically used to filter out features. Tried with several other units and combination of layers (dropout and other dense layers) but none yield better results
    6. The dense layer makes use of the ‘relu’ activation. This activation was recommended in the Udacity course because training is faster and overall gives the best results. I tried all other available activations like ‘selu’ and ‘softplus’. Some did at times provide better test results, but the results differed significantly from one test to the other despite setting a random seed.
    7. The next layer added is a Batch Normalization layer. This layer is used to normalize the data. This is a technique helps train the network faster and improve the results.
    8. The last layer is a dense layer with 10 units. The units should match the number of classification we need. This is common practice in CNN’s.
    9. A ‘softmax’ activation is used in the last dense layer because it yields the best results for a multi classification problem. I tried and tested with other activation functions, but no activation does better.
    10. The model architecture is then compiled with the optimizer ‘SGD’. This optimizer was selected after looking through all available optimizers.
    11. The ‘SGD’ optimizer has the learning rate of 0.001. At this speed the optimizer learns important features rather quickly. If we were not to apply Batch Normalization, we would need to reduce the learning rate to 0.0009.
    12. Applying a Momentum of 0.9 to our optimizer simply aims to speed up the learning process.
    13. Applying the Nesterov parameter enhances the momentum parameter into reaching the best results even faster.

To verify the robustness of the final model, I tested the model on the Kaggle test dataset and submitted it. The model can be considered robust and good at generalizing unseen data if it is able to yield decent results on a total of 79726 unseen images. I was unable to provide my own images because I just recently moved to another country and there I do not own a vehicle. Small changes (aside from the necessary data augmentations) on the train data does significantly impact (negatively) the end results because these changes would impact key features the model is trying to learn.

* 1. **Justification**

The final results are found stronger than the benchmark result reported earlier. The model results to a log loss of (value) while the benchmark has a log loss of (value). This means that model would be able to solve the problem only (value difference) better than the benchmark. The model does not do significant better than the benchmark, but it is certainly enough to categorize drivers into the 10 behaviors with minimal error.

1. **Conclusion(1-2 pages)**
   1. **Free-form Visualization**
   2. **Reflection**

This may serve as a summary of the entire process I used for this project

* + 1. Find a relevant problem that machine learning can solve
    2. Understand the data input
    3. Research similar problems and their solutions
    4. Identify the most efficient high-level solution for the problem
    5. Create a benchmark result
    6. Implement a simple solution
    7. Identify problems areas that stop implementation from reaching desired results.
    8. Research and list down solutions to the problems listed
    9. Test each solution
    10. Apply and refine working solutions
    11. Iterate steps 6 to 10 until satisfied with results

The most interesting aspects of this project are:

1. Understanding all the different techniques and optimizations to solve the problem.
2. Importance of understanding the logic behind each parameter.

The most difficult aspects of this project are:

1. Trying to achieve optimal results was a real challenge. I had to make use of all the best practices and optimizations I could find before I could get even close to the benchmark result.
2. Another complicated aspect of this project was the cause and effect. An example of this is that by changing parameter A, I would have space to optimize parameter B but doing so would negatively affect parameter C. Trial and error was key to helping me understand the relationship of one parameter to the other.
3. Another difficult aspect of this project was fitting data into memory. I spent weeks trying to implement all sorts of memory optimization techniques, but they were all just not enough. Of course, I could have just reduced the image size, removed some image augmentations and submitted the project with sub-optimal results. But because I really wanted to achieve the results I committed to, I resorted to buying an additional 8 GB of RAM and when that wasn’t enough during the K-fold implementation I bought another 8 GB. Even then I used to still run into memory issues, but it was at least enough to get the job done.

The final model met my expectations for the problem and I believe there are many techniques and optimizations used here that would work on similar problems.

* 1. **Improvement**

If I were to use my solution as the new benchmark, beating it would certainly be a challenge. However, there are some solutions that are significantly better than this one as we can see from the Kaggle leaderboard, but it would require someone with either more experience, better equipment or more time.

There are some improvements that would have worked had I known how to implement them. I would have tried studying these methods, but I ran out of money to extend the course. I will however try to properly implement them after passing this project. These are the improvements that would have worked:

* + 1. One technique is using multiple models. This technique is used to improve the generalization and overall prediction accuracy by averaging out the results of multiple models. I tried implementing a version of this, but it did not work out. I assume its because both models were learning the same features and used similar parameters. Training multiple models on different portions of the image would have yield better results.
    2. Another technique is the freezing of layers and retraining them.
    3. Hiding unimportant portions of the image. This would help the model learn only the important parts of the image. In theory it should improve the training speed and increase the accuracy.
    4. Rescaling images closer to its original size. Important features may have been lost by rescaling them to a 224 x 224 and I did not have the necessary hardware to effectively test this.
    5. Decreasing the batch size. In theory, the model would learn more features at the cost of training time.

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