Autonomous Parking Space Analysis

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Overview

Description

The project aims to automatically predict the availability of a parking spot given the feeds provided by a video camera monitoring the parking area.

Motivation

Hunting for parking brings no joy for students[1]

"...Students at Wits are struggling to find available parking spaces on campuses since..."
"...student X said that finding parking is the biggest issue she faces at Wits."

— Aarti Bhana, Wits Vuvuzela

Problems

Various factors can explain the parking space problems mostly in urban areas:

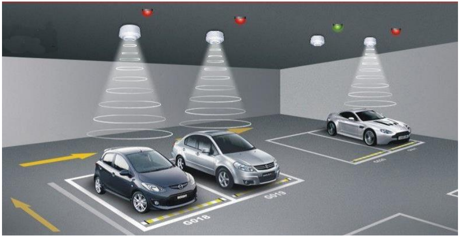
- Urban planning not following the quick growth of population dynamics
- Drivers not aware of available space due to lack of knowledge of the area or anything obstructing it from the driver
- Bad management of the parking area

Aims

This project aims to:

- Perform comparative study between existing solutions (SVM based algorithms) and CNN,
- Use video cameras to allocate parking spaces to drivers
- Apply computer vision techniques to infer the status of a space (Background subtraction, Hough transform ...),
- Help the driver to locate a vacant spot using the dedicated web application,
- Run a quantitative analysis of the results produced by the system to predict parking habits of drivers.

Sensors Based Detection



Non-intrusive sensors, [2]

Intrusive sensors, [3]

Sensors Based Detection

Pros:

- Very accurate,
- Since individually installed per spot, the system can return the available number of spots [4],
- Almost no computation required

Cons:

- Expensive in installation in terms of number of devices to place per spot,
- Expensive in maintenance.

Traditional Image Processing

1. Background subtraction to create a transience map of the parking area or to model the parking area given the previous positions of vehicles
2.

Background Subtraction I

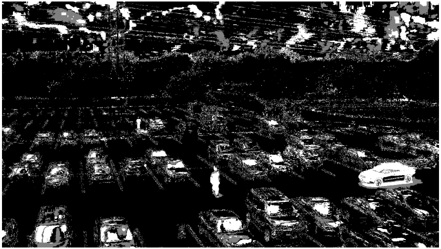
Definition

The background subtraction is a technique used in computer vision and image processing for detecting the foreground from a set a images of the same scenario (video sequence of a non-moving camera) for various types of detection problems.

$$pixel\_value = \begin{cases} 1, & |frame_i - frame_{i-1}| > T_h \\ 0, & \text{otherwise} \end{cases}$$

Background Subtraction II

Original image

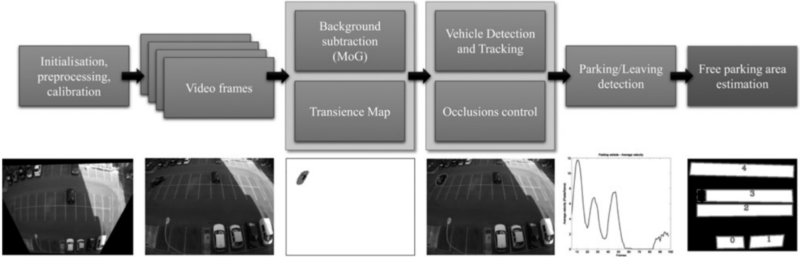


Background subtracted image

Background Subtraction III

Background subtraction to:

- Create a transience map of the parking area or to model the parking area given the previous positions of vehicles [5]



Background subtraction method proposed by [5]

This method used the background subtraction and the Mixture of Gaussians to detect and track vehicles to infer the availability of remaining spots given a **threshold** on the transient value,

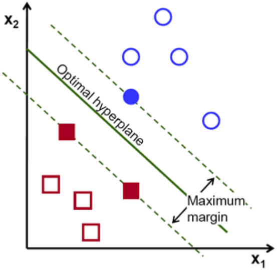
Background Subtraction IV

- Use histograms of spatial features to map the spots of an unmanaged parking area but taking as object the group of pixels generated by vehicles, rejecting the non-vehicle objects by automatically adjusting the **threshold** [6].

Support Vector Machines I

Definition:
Supervised machine learning technique that is based on a decision boundary to separate data into different subsets (classes). Support vectors are the coordinates of data point in the data space that are the closest to the boundary lines, hyperplanes.
Support Vector Machines(SVM) can be used for **classification** and **regression** problems. The classification has been mostly used for the parking space detection.

Support Vector Machines II

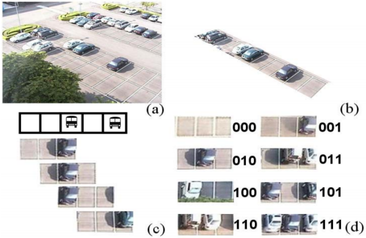


Support Vector Machines, OpenCVDocs

Support Vector Machines (SVM) have been widely used for the problem.
Usually associated with Histograms of Oriented Gradients (HoG), Difference of Gaussians (DoG), color histograms, Local Binary Patterns...
SVMs to:

Support Vector Machines III

- Detect available parking spaces using both multi-class Support Vector Machines (SVMs) and a Markov Random Field (MRF) framework using the color histograms as features [7] with an accuracy of 93.52%,



Multi-class SVM, [7]

- Classify individual spot using DoG- features with an accuracy of 92.33 after a comparative study with the k-NN, LDA and HoG, RGB, HSV YUV (color spaces) as features [8]%

Support Vector Machines IV

- As similar to the previous point, classify individual spot using Local Binary Patterns and Local Phase Quantization as features with an accuracy of 99% [9].

(a) (b) (c)

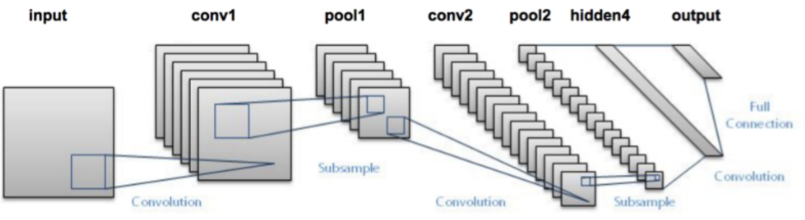
Segmented image, [9]

Deep Learning - Convolutional Neural Networks

Definition

- Spervised branch of machine learning for pattern and object recognition,
- CNN learn extracted features,
- CNN are computationally expensive at the training phase especially when the dataset contains many classes with many objects to classify

Deep Learning - Convolutional Neural Networks



Lenet-5, [10]

Path to follow

Guidelines

Our main objectives will be to:

- Compare the performance of the mainly used classifiers based on the literature review: CNN and SVM,
- Collect data for the new experiments to do based on the classifier we will choose,
- Design and implement an algorithm that will automatically withdraw the parking bays to feed them to the classifier (Hough transform for example) given the whole parking lot
- Perform a qualitative analysis of the usage of the parking as a whole to predict the availability of the bays.

End

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