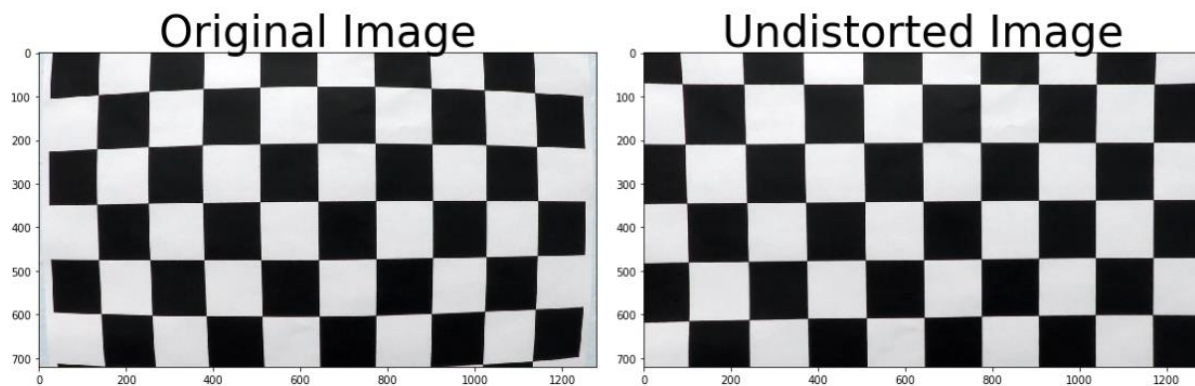


This is the write-up report for project4 Advanced Lane Finding.

Camera Calibration

Camera calibration is done using all images located in 'camera_cal/' folder. The code for camera calibration is in first cell of ipython notebook, "P4.ipynb." This section is pretty straight forward, all same steps like in lectures.

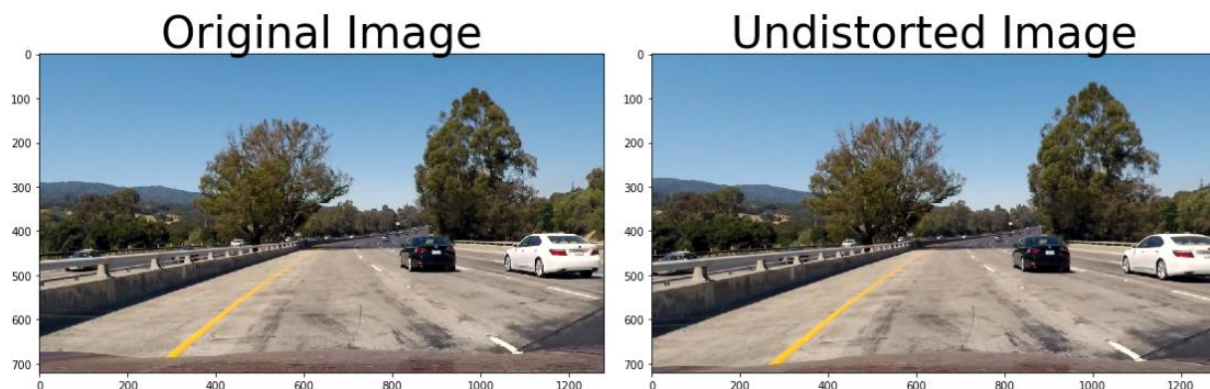
"Corners" points are obtained from `cv2.findChessboardCorners` to create "objpoints" and "imgpoints." These corner points are fed into `cv2.calibrateCamera` to get "mtx" and "dist" that needed to undistort image with `cv2.undistort`.



This camera calibration step is actually included in `lane_coloring()`, not in `pipeline()` due to the pipeline structure. This is because I started off from this function, and stuck with this naming convention. It is easier to be understood that `pipeline()` is actually a filtering function for image thresholds explained in next section.

Pipeline (single images)

1. Provide an example of a distortion-corrected image.



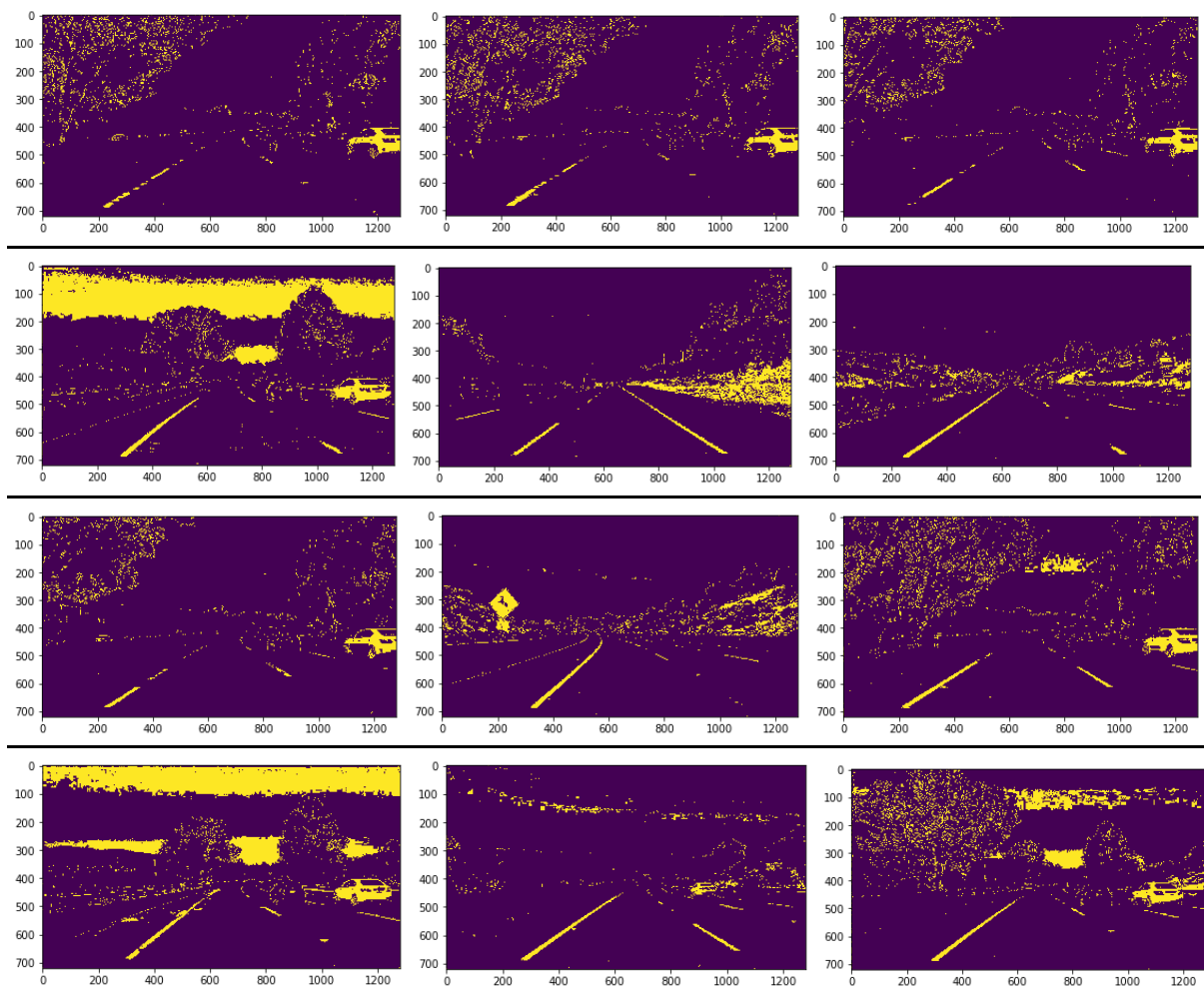
Above images are the outcome of camera distortion correction.

2. Describe how (and identify where in your code) you used color transforms, gradients or other methods to create a thresholded binary image. Provide an example of a binary image result.

There are several color transform methods are mixed together.

- L-channel from HLS color channels
- HSV filter recycled from Project1; Grayscale image from `filter()` >150
- Simple RGB filtering condition with $R > 150$, $G > 100$, $B < 100$.

Usage of s-channel and sobel x gradient was also considered, but dropped eventually because I found out it gives bad result on some section of project video – where the shadow from tree and road color changes drastically. Following is the list of output images from combination of above methods. Test images include all images in “test_images” folder and some frame captured from 40~42nd sec.



```

test_images_output/frame1038.jpg
test_images_output/frame1039.jpg
test_images_output/frame1040.jpg
test_images_output/frame1041.jpg
test_images_output/frame1042.jpg
test_images_output/frame1043.jpg
test_images_output/straight_lines1.jpg
test_images_output/straight_lines2.jpg
test_images_output/test1.jpg
test_images_output/test2.jpg
test_images_output/test3.jpg
test_images_output/test4.jpg
test_images_output/test5.jpg
test_images_output/test6.jpg

```

3. Describe how (and identify where in your code) you performed a perspective transform and provide an example of a transformed image.

```

imshape = img.shape
x1 = int(imshape[1]/2 - 120)
x2 = int(imshape[1]/2 + 120)
y1 = int(imshape[0]/2 + 120)
y2 = int(imshape[0])

if img is not None:

    src = np.float32([[100,y2-40],[x1, y1],[x2, y1],[imshape[1]-100,y2-40]])
    dst = np.float32([[300,720],[300,0],[980,0],[980,720]])

```

Most coordinates of perspective transform source (src) are calculated based on size of image (Bottom 40 pixels are removed due to the hood of the vehicle), and most of destination (dst) are hardcoded on the other hand.

To summarize, following table is the source and destination coordinates.

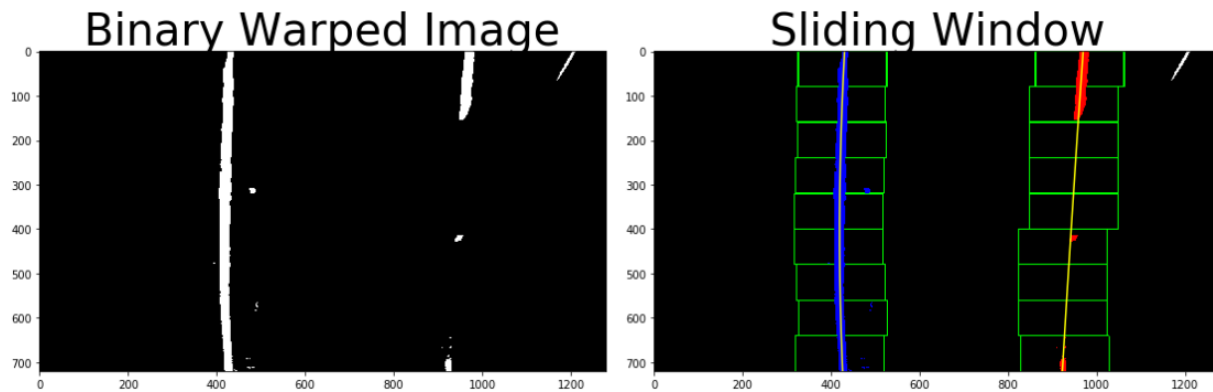
Source	Destination
100, 680	300, 720
520, 480	300, 0
760, 480	980, 0
1180, 680	980, 720

And following is the result of perspective transform.

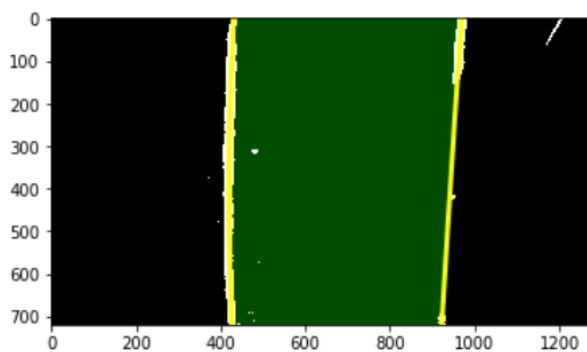



4. Describe how (and identify where in your code) you identified lane-line pixels and fit their positions with a polynomial?

Similar to the lectures, I performed sliding window method and polynomial to fit the lane lines.



Then, I filled the regions in between of lanes with `cv2.fillPoly`, converted this binary back with unwarp process by performing perspective transform with src and dst swapped.



```
# Unwarp to transform coloring back to camera perspective
M1 = cv2.getPerspectiveTransform(dst, src)
unwarp = cv2.warpPerspective(weighted, M1, img_size, flags=cv2.INTER_LINEAR)
 = cv2.cvtColor(img, cv2.COLOR_BGR2RGB) #Uncomment for images
colored = cv2.addWeighted(img, 1, unwarp, 0.8, 0)
```

5. Describe how (and identify where in your code) you calculated the radius of curvature of the lane and the position of the vehicle with respect to center.

Lane curvature calculation is in the middle of `lane_coloring()` pipeline from line 68~100, and position of vehicle is from lane 116~130.

Position is simply calculated base on the average of bottom values (closest to the vehicle, `yvalue = img.shape[0]`) of two curvatures, assuming the camera is perfectly centered. Thus, if this value is greater than mid point (`x:640`), then it's off to right side with deviation distance `dist = abs((ctr_p - 640)*xm_per_pix)` where `xm_per_pix` is given as 3.7m/700 pixels.

6. Provide an example image of your result plotted back down onto the road such that the lane area is identified clearly.



Image test results can be populated with following,

```
# Testing lane_coloring() on images
test_dir = './test_images/'
output_dir = './test_images_output/'
files = os.listdir(test_dir)

for file in files:
    image = mpimg.imread(test_dir + file)
    output = lane_coloring(image)
    filename = output_dir + file

    os.makedirs(os.path.dirname(filename), exist_ok=True)
    cv2.imwrite(filename, output)
```

And video with following code cell, both included in P4.ipynb

```
from moviepy.editor import VideoFileClip
from IPython.display import HTML
import os

output = 'test_videos_output/project_output.mp4'

clip = VideoFileClip("project_video.mp4")#.subclip(40,42)
processed_clip = clip.fl_image(lane_coloring)
```

Discussion

1. Briefly discuss any problems / issues you faced in your implementation of this project. Where will your pipeline likely fail? What could you do to make it more robust?

A few things I noticed was that the curvature/vehicle position calculation is very sensitive base on values of perspective transform and color thresholds. Also, there is a room for further improvement with adaptive thresholding although I managed to complete it with a combination of static thresholds. The pipeline might still likely fail if there was any yellowish/white vehicle nearby within the camera range.