# MAE 198 A

## Team #3
## DonkeyCar with Line Detection

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# Progress

- Camera angle adjusted to maximize road in field of view
- Several iterations of neural nets trained
    - Varying times + lighting conditions
    - Varying position of car in road (left of divider, centered on divider)
- Issues
    - Car has difficulty correcting errors
    - Lighting obfuscates lines in camera images
    - PS3 Controller finicky and requires frequent reconnection

# Directions

- Create training sets with error correction
- Pre-process images to filter out noise
- Use pre-existing API for donkeycar to pipe filtered image into neural network
- Explore fine-tuning pretrained net