UDACITY

PROJECT

Finding Lane Lines on the Road

A part of the Self Driving Car Engineer Nanodegree Program

PROJECT REVIEW

NOTES

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Meets Specifications

Hi there!

Congrats on taking the first step in the Self Driving Nano degree. I hope you enjoyed working through the project and developed a basic intuition on how to go about lane detection. I have added few suggestions and resources which will improve your understanding and make the project more robust.

All the best for the future projects 😄

PS: If you have not already joined the slack community, please do so by going here

Lane Finding Pipeline

The output video is an annotated version of the input video.

The output video is an annotated version of the input video. Well done 👍

For your canny function, canny(img, low_threshold, high_threshold): in particular the values low_threshold and high_threshold, these parameter values enable the canny edge detector to analyse a region within the video, for optimum region_of_interest, I would recommend these values: low_threshold = 50, high_threshold = 150.

Really excited when reading your code, I quite enjoyed how you tested various parameters on the images, the reduced region of interest, and also the "Hough Lines" test! You've managed to successfully test various values for the parameters and chosen the correct values for optimum output, your video "white.mp4" gives me the assumption that the value you use for the gaussian_blur function in particular "kernel_size" = 5, you have also realised that it being odd is inadmissible, this is because the value 3, 5, 7, 9... for this particular domain blurs the image to the right amount for the Gaussian Filter to be optimum. However, to reduce noise, I would slightly reduce the kernel_size value to 3.

In a rough sense, the left and right lane lines are accurately annotated throughout almost all of the video. Annotations can be segmented or solid lines

Well done. The left and right lane lines are accurately annotated throughout almost all of the video.

Visually, the left and right lane lines are accurately annotated by solid lines throughout most of the video.

The left and right lane lines were annotated throughout almost all of the video. ou can improve it by drawing solid lane lines.

Reflection

Reflection describes the current pipeline, identifies its potential shortcomings and suggests possible improvements. There is no minimum length. Writing in English is preferred but you may use any language.

Great intuitions and understanding. You have correctly explained the shortcomings and potential improvements. 👍

Few points to think upon

- Can a different colour space be used to make the pipeline more robust.
- I encourage you to try and tune the parameters. For starters you can refer to the algorithm discussed here

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