P1

October 21, 2020

1 Self-Driving Car Engineer Nanodegree

1.1 Project: Finding Lane Lines on the Road

In this project, you will use the tools you learned about in the lesson to identify lane lines on the road. You can develop your pipeline on a series of individual images, and later apply the result to a video stream (really just a series of images). Check out the video clip "raw-lines-example.mp4" (also contained in this repository) to see what the output should look like after using the helper functions below.

Once you have a result that looks roughly like "raw-lines-example.mp4", you'll need to get creative and try to average and/or extrapolate the line segments you've detected to map out the full extent of the lane lines. You can see an example of the result you're going for in the video "P1_example.mp4". Ultimately, you would like to draw just one line for the left side of the lane, and one for the right.

In addition to implementing code, there is a brief writeup to complete. The writeup should be completed in a separate file, which can be either a markdown file or a pdf document. There is a write up template that can be used to guide the writing process. Completing both the code in the Ipython notebook and the writeup template will cover all of the rubric points for this project.

The tools you have are color selection, region of interest selection, grayscaling, Gaussian smoothing, Canny Edge Detection and Hough Tranform line detection. You are also free to explore and try other techniques that were not presented in the lesson. Your goal is piece together a pipeline to detect the line segments in the image, then average/extrapolate them and draw them onto the image for display (as below). Once you have a working pipeline, try it out on the video stream below.

Your output should look something like this (above) after detecting line segments using the helper functions below

Your goal is to connect/average/extrapolate line segments to get output like this

Run the cell below to import some packages. If you get an `import error` for a package you've already installed, try changing your kernel (select the Kernel menu above --> Change Kernel). Still have problems? Try relaunching Jupyter Notebook from the terminal prompt. Also, consult the forums for more troubleshooting tips.

1.2 Import Packages

```
In [7]: #importing some useful packages
        import matplotlib.pyplot as plt
        import matplotlib.image as mpimg
        import numpy as np
        import cv2
        %matplotlib inline
```

1.3 Read in an Image

```
In [8]: #reading in an image
        image = mpimg.imread('test_images/solidWhiteRight.jpg')

        #printing out some stats and plotting
        print('This image is:', type(image), 'with dimensions:', image.shape)
        plt.imshow(image)  # if you wanted to show a single color channel image called 'gray', f
```

```
This image is: <class 'numpy.ndarray'> with dimensions: (540, 960, 3)
```

```
Out[8]: <matplotlib.image.AxesImage at 0x7f3105b8f240>
```

1.4 Ideas for Lane Detection Pipeline

Some OpenCV functions (beyond those introduced in the lesson) that might be useful for this project are:

`cv2.inRange()` for color selection
`cv2.fillPoly()` for regions selection

`cv2.line()` to draw lines on an image given endpoints
`cv2.addWeighted()` to coadd / overlay two images `cv2.cvtColor()` to grayscale or change color
`cv2.imwrite()` to output images to file
`cv2.bitwise_and()` to apply a mask to an image

Check out the OpenCV documentation to learn about these and discover even more awesome functionality!

1.5 Helper Functions

Below are some helper functions to help get you started. They should look familiar from the lesson!

```
In [10]: import math

         prev_slop = [-100,-100,-100,-100]

         def grayscale(img):
             """Applies the Grayscale transform
             This will return an image with only one color channel
             but NOTE: to see the returned image as grayscale
             (assuming your grayscaled image is called 'gray')
             you should call plt.imshow(gray, cmap='gray')"""
             return cv2.cvtColor(img, cv2.COLOR_RGB2GRAY)
             # Or use BGR2GRAY if you read an image with cv2.imread()
             # return cv2.cvtColor(img, cv2.COLOR_BGR2GRAY)

         def canny(img, low_threshold, high_threshold):
             """Applies the Canny transform"""
             return cv2.Canny(img, low_threshold, high_threshold)

         def gaussian_blur(img, kernel_size):
             """Applies a Gaussian Noise kernel"""
             return cv2.GaussianBlur(img, (kernel_size, kernel_size), 0)

         def region_of_interest(img, vertices):
             """
             Applies an image mask.

             Only keeps the region of the image defined by the polygon
             formed from `vertices`. The rest of the image is set to black.
             `vertices` should be a numpy array of integer points.
             """
             #defining a blank mask to start with
             mask = np.zeros_like(img)

             #defining a 3 channel or 1 channel color to fill the mask with depending on the inp
             if len(img.shape) > 2:
                 channel_count = img.shape[2]  # i.e. 3 or 4 depending on your image
```

```
        ignore_mask_color = (255,) * channel_count
    else:
        ignore_mask_color = 255

    #filling pixels inside the polygon defined by "vertices" with the fill color
    cv2.fillPoly(mask, vertices, ignore_mask_color)

    #returning the image only where mask pixels are nonzero
    masked_image = cv2.bitwise_and(img, mask)
    return masked_image

def group_lane_linens(lines):
    left  = np.zeros(4,dtype=np.float32) # x_b,y_b,x_t,y_t
    right = np.zeros(4,dtype=np.float32) # x_b,y_b,x_t,y_t
    num_l = 0
    num_r = 0
    for line in lines:
        #group the identfied lines into left and right lane group based on slope
        for x1,y1,x2,y2 in line:
            if ((y2-y1)/(x2 -x1)) < 0:
                num_l +=1
                left[0] += x1
                left[1] += y1
                left[2] += x2
                left[3] += y2
            else:
                num_r +=1
                right[0] += x1
                right[1] += y1
                right[2] += x2
                right[3] += y2
    return num_l,num_r,left,right

def compute_lane_slope(points,num,curr_w,prev_w,y_size,leftorright):
    # compute the slope for the line
    m,b = np.polyfit((points[0]/num,points[2]/num),(points[1]/num,points[3]/num),1)
   # the new slope and intercept is averaged with the previous slop to avoid sudden jun
    if(prev_slop[0+2*leftorright] != -100):
        m = m*curr_w + prev_w*prev_slop[0+leftorright*2]
        b = b*curr_w + prev_w*prev_slop[1+leftorright*2]

    x_b= int((y_size - b)/m)
    x_t= int((y_size*0.6- b)/m)
    return x_b,x_t,m,b

def draw_lines(img, lines, color=[255, 0, 0], thickness=2):
    """
    NOTE: this is the function you might want to use as a starting point once you want
```

```
    average/extrapolate the line segments you detect to map out the full
    extent of the lane (going from the result shown in raw-lines-example.mp4
    to that shown in P1_example.mp4).

    Think about things like separating line segments by their
    slope ((y2-y1)/(x2-x1)) to decide which segments are part of the left
    line vs. the right line.  Then, you can average the position of each of
    the lines and extrapolate to the top and bottom of the lane.

    This function draws `lines` with `color` and `thickness`.
    Lines are drawn on the image inplace (mutates the image).
    If you want to make the lines semi-transparent, think about combining
    this function with the weighted_img() function below
    """
    curr_w = 0.9  #current slope weight
    prev_w = 0.1  #previous slope weight
    y,x,z = img.shape
    num_l,num_r,left,right = group_lane_linens(lines)
    #print("right: ",right)
    if(num_l > 0): #left lane group
        x_b,x_t,m,b = compute_lane_slope(left,num_l,curr_w,prev_w,y,0)
        if(x_t > 0.4*x and x_t<0.5*x):
            prev_slop[:2] = m,b
            cv2.line(img, (x_b, y), (x_t, int(y*0.6)), color, thickness)
    if(num_r > 0): #right lane group
        x_b,x_t,m,b = compute_lane_slope(right,num_r,curr_w,prev_w,y,1)
        #print("right: ", x_b,x_t,m,b,num_r)
        if(x_t > 0.5*x and x_t<0.6*x):
            prev_slop[2:] = m,b
            cv2.line(img, (x_b, y), (x_t, int(y*0.6)), color, thickness)


def hough_lines(img, rho, theta, threshold, min_line_len, max_line_gap):
    """
    `img` should be the output of a Canny transform.

    Returns an image with hough lines drawn.
    """
    lines = cv2.HoughLinesP(img, rho, theta, threshold, np.array([]), minLineLength=min
    line_img = np.zeros((img.shape[0], img.shape[1], 3), dtype=np.uint8)
    draw_lines(line_img, lines)
    return line_img

# Python 3 has support for cool math symbols.

def weighted_img(img, initial_img, =0.8, =1., =0.):
    """
    `img` is the output of the hough_lines(), An image with lines drawn on it.
```

```
    Should be a blank image (all black) with lines drawn on it.

    `initial_img` should be the image before any processing.

    The result image is computed as follows:

    initial_img * α + img * β + γ
    NOTE: initial_img and img must be the same shape!
    """
    return cv2.addWeighted(initial_img, α, img, β, γ)
```

1.6 Test Images

Build your pipeline to work on the images in the directory "test_images"
You should make sure your pipeline works well on these images before you try the videos.

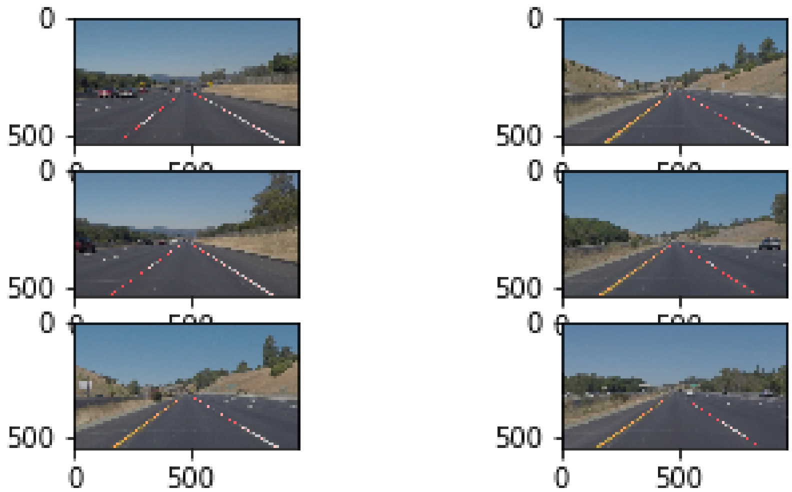
```
In [11]: import os
         #os.listdir("test_images/")
```

1.7 Build a Lane Finding Pipeline

Build the pipeline and run your solution on all test_images. Make copies into the `test_images_output` directory, and you can use the images in your writeup report.

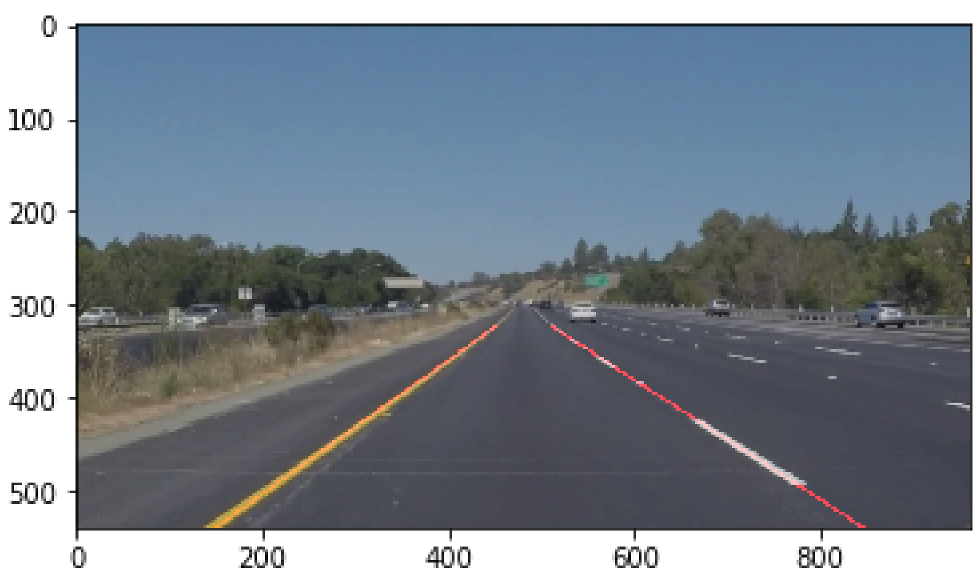
Try tuning the various parameters, especially the low and high Canny thresholds as well as the Hough lines parameters.

```
In [12]: # TODO: Build your pipeline that will draw lane lines on the test_images
         # then save them to the test_images_output directory.
         test_images = os.listdir("test_images/")
         i = 0
         prev_slop = [-100,-100,-100,-100]
         for test_img in test_images:
             image_test = np.copy(mpimg.imread('test_images/'+test_img))
             y,x,z = image_test.shape
             image_gray = grayscale(image_test)
             image_gaus = gaussian_blur(image_gray,5)
             image_cany = canny(image_gaus,50,120)
             ver = np.array([[(0,y),(int(x/2),int(y*0.56)),(int(x/2),int(y*0.56)),(x,y)]])
             #print(ver)
             image_roi = region_of_interest(image_cany,ver)
             image_lines = hough_lines(image_roi,2,np.pi/180,1,30,10)
             image_res = weighted_img(image_lines,image_test)
             plt.subplot(len(test_images) / 2 + 1, 2, i + 1)
             plt.imshow(image_res)
             i +=1
             #plt.imshow()
         #plt.imshow(image_lines)
```



In [13]:
```
plt.imshow(image_res)
```

Out[13]:
```
<matplotlib.image.AxesImage at 0x7f3101f9f160>
```



1.8 Test on Videos

You know what's cooler than drawing lanes over images? Drawing lanes over video!

We can test our solution on two provided videos:

`solidWhiteRight.mp4`

solidYellowLeft.mp4

Note: if you get an import error when you run the next cell, try changing your kernel (select the Kernel menu above --> Change Kernel). Still have problems? Try relaunching Jupyter Notebook from the terminal prompt. Also, consult the forums for more troubleshooting tips.

If you get an error that looks like this:

```
NeedDownloadError: Need ffmpeg exe.
You can download it by calling:
imageio.plugins.ffmpeg.download()
```

Follow the instructions in the error message and check out this forum post for more troubleshooting tips across operating systems.

```
In [14]: # Import everything needed to edit/save/watch video clips
         from moviepy.editor import VideoFileClip
         from IPython.display import HTML
```

```
In [15]: def process_image(image):
             # NOTE: The output you return should be a color image (3 channel) for processing vi
             # TODO: put your pipeline here,
             # you should return the final output (image where lines are drawn on lanes)
             y,x,z = image.shape
             image_gray = grayscale(image)
             image_gaus = gaussian_blur(image_gray,3)
             image_cany = canny(image_gaus,60,150)
             ver = np.array([[(0,y),(int(x/2),int(y*0.6)),(int(x/2),int(y*0.6)),(x,y)]])
             #print(ver)
             image_roi = region_of_interest(image_cany,ver)
             image_lines = hough_lines(image_roi,2,np.pi/180,1,40,10)
             image_res = weighted_img(image_lines,image)

             return image_res
```

Let's try the one with the solid white lane on the right first ...

```
In [16]: prev_slop = [-100,-100,-100,-100]
         white_output = 'test_videos_output/solidWhiteRight.mp4'
         ## To speed up the testing process you may want to try your pipeline on a shorter subcl
         ## To do so add .subclip(start_second,end_second) to the end of the line below
         ## Where start_second and end_second are integer values representing the start and end
         ## You may also uncomment the following line for a subclip of the first 5 seconds
         ##clip1 = VideoFileClip("test_videos/solidWhiteRight.mp4").subclip(0,5)
         clip1 = VideoFileClip("test_videos/solidWhiteRight.mp4").subclip(0,5)
         white_clip = clip1.fl_image(process_image) #NOTE: this function expects color images!!
         %time white_clip.write_videofile(white_output, audio=False)
```

```
[MoviePy] >>>> Building video test_videos_output/solidWhiteRight.mp4
[MoviePy] Writing video test_videos_output/solidWhiteRight.mp4
```

```
 99%|| 125/126 [00:06<00:00, 16.56it/s]


[MoviePy] Done.
[MoviePy] >>>> Video ready: test_videos_output/solidWhiteRight.mp4

CPU times: user 1.24 s, sys: 112 ms, total: 1.36 s
Wall time: 7.79 s
```

Play the video inline, or if you prefer find the video in your filesystem (should be in the same directory) and play it in your video player of choice.

```
In [17]: HTML("""
         <video width="960" height="540" controls>
           <source src="{0}">
         </video>
         """.format(white_output))

Out[17]: <IPython.core.display.HTML object>
```

1.9 Improve the draw_lines() function

At this point, if you were successful with making the pipeline and tuning parameters, you probably have the Hough line segments drawn onto the road, but what about identifying the full extent of the lane and marking it clearly as in the example video (P1_example.mp4)? Think about defining a line to run the full length of the visible lane based on the line segments you identified with the Hough Transform. As mentioned previously, try to average and/or extrapolate the line segments you've detected to map out the full extent of the lane lines. You can see an example of the result you're going for in the video "P1_example.mp4".

Go back and modify your draw_lines function accordingly and try re-running your pipeline. The new output should draw a single, solid line over the left lane line and a single, solid line over the right lane line. The lines should start from the bottom of the image and extend out to the top of the region of interest.

Now for the one with the solid yellow lane on the left. This one's more tricky!

```
In [18]: yellow_output = 'test_videos_output/solidYellowLeft.mp4'
         ## To speed up the testing process you may want to try your pipeline on a shorter subcl
         ## To do so add .subclip(start_second,end_second) to the end of the line below
         ## Where start_second and end_second are integer values representing the start and end
         ## You may also uncomment the following line for a subclip of the first 5 seconds
         ##clip2 = VideoFileClip('test_videos/solidYellowLeft.mp4').subclip(0,5)
         prev_slop = [-100,-100,-100,-100]
         clip2 = VideoFileClip('test_videos/solidYellowLeft.mp4')
         yellow_clip = clip2.fl_image(process_image)
         %time yellow_clip.write_videofile(yellow_output, audio=False)

[MoviePy] >>>> Building video test_videos_output/solidYellowLeft.mp4
[MoviePy] Writing video test_videos_output/solidYellowLeft.mp4
```

```
100%|| 681/682 [00:42<00:00, 15.54it/s]


[MoviePy] Done.
[MoviePy] >>>> Video ready: test_videos_output/solidYellowLeft.mp4

CPU times: user 6.84 s, sys: 781 ms, total: 7.62 s
Wall time: 44 s
```

```
In [19]: HTML("""
         <video width="960" height="540" controls>
           <source src="{0}">
         </video>
         """.format(yellow_output))

Out[19]: <IPython.core.display.HTML object>
```

1.10 Writeup and Submission

If you're satisfied with your video outputs, it's time to make the report writeup in a pdf or markdown file. Once you have this Ipython notebook ready along with the writeup, it's time to submit for review! Here is a link to the writeup template file.

1.11 Writeup Template

1.11.1 You can use this file as a template for your writeup if you want to submit it as a markdown file. But feel free to use some other method and submit a pdf if you prefer.

Finding Lane Lines on the Road

The goals / steps of this project are the following: * Make a pipeline that finds lane lines on the road * Reflect on your work in a written report

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1.11.2 Reflection

1.11.3 1. Describe your pipeline. As part of the description, explain how you modified the draw_lines() function.

The pipeline implemented consists of 5 steps. First, the input image is converted to grayscale, then a Gaussian smoothing operation is applied to suppress noises. As the third step, canny edge detection is applied to the smoothed image to extract edges. Next, instead of finding lines on the entire image, a region of interest operation is performed to identify the regions we are interested to extract lane lines. Finally, using Hough transforms the possible set of lane lines are identified.

In order to draw a single line on the left and right lanes, I modified the draw_lines() function to group the possible set of lines into left and right lane lines based on the slope of the line (see group_lane_linens()). Then by averaging the slope and the intercept of each group of lines, the