# JRD 301: Mini Project in Robotics (Second Semester 2019‐20)

Weekly Progress Report (From: 20/1/2020 To: 24/1/2020)

I undertake that the following work has been accomplished during the above mentioned period of one week (please write in bulleted points):

* In order to reduce the variations of the centres, we ignored the values of centres that were more than a specified distance from the initial value as such a variation meant incorrect centre. But this only reduced incorrect values but didn’t reduce the variation of points.
* To solve this issue, we created a contour around the heading direction and only gave a steering angle if centre of road outside the contour. This reduced the variations of very nearby points but not which were a bit far.
* Also in this approach if the centre is in some case stored at a side, then its correction was issue as the initial value was wrong. So we had no correct basis to measure distance.
* We also tried to follow the approach of one sided lane detection(left). But it gave not very good results as had a lot of variations and incorrections. It was also dependent on road width and was a problem when one side had no lane marks. It was also a problem at turns and roundabouts where only one side had lane marks.

# A close up of a road Description automatically generatedA view of a city street Description automatically generated

# *Fig1. One-sided lane detection results*

# Submitted by (student’s name with signature) Endorsed by:

Group member 1: Harman Mehta (2016BB50003) Supervisor 1: Prof. Sunil Jha

Group member 2: Tanmay Goyal (2016ME20757)