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

Weekly Progress Report (From: 13/1/2020 To: 17/1 /2020)

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

* We divided the frame into lower and upper half by frame coordinates -
  + Upper half – We used only the upper half of the frame for the lane detection. This allowed us to neglect all the horizontal lines that are encountered from the front of the car. This is the used to predict the direction of motion.(blue lines)
  + Lower half – We used the lower half of the frame for detecting the horizontal line on the front of the car to detect the car centre. By it we got the heading direction of the car. This heading direction of car was independent of the width of road and frame we selected.(green lines)
* ![A close up of a street

  Description automatically generated]()But the centre of the car and the road we calculated from this varied highly because of certain wrongly identified line giving incorrect values. This made the car wobble a lot.

# *Fig1. two frames separated*

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

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