1. Algorithm Implementation:
   1. Data Preprocessing:
      1. Assign values to variables

The prototxt and caffemodel of MobileNetSSD is loaded and assigned to a variable. Other variables like height of the frame, confidence value for neural net, maximum distance to track the object, etc.

* + 1. Resize image

Large image takes longer time to process. So the images are resized before processing to the appropriate height.

* 1. Object Detection, Classification and Tracking:
     1. Blob

kjanldflvakjfkvadd

* + 1. MobileNetSSD

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* + 1. Centroid Tracking Algorithm:

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* 1. Violation Checking:

Each of the tracked objects is assigned two variables that checks whether the object is violating the rule of stopping on red light or not. As we know, this violation should only be checked in red light and not on green and yellow light. This event is stimulated by checking the violation for a minute and not checking for other two minutes. The variables are:

1. A Boolean variable that determines whether the vehicle is going up or down. Assuming that the camera is in front of the place where the vehicle has to stop, we can ignore the vehicle going up and only check for vehicle going down.
2. A Boolean variable that determines whether the vehicle is above or below the line. A vehicle which is already below the line cannot violate this rule.

If the vehicle is going down and above the line in red light and crosses the line, the vehicle has violated the rule.