Behavioral Cloning

End to End Learning for self-driving cars

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The goals / steps of this project are the following:

\* Use the simulator to collect data of good driving behavior (I don't have a hand shank and use keyboard to train the simulator is quite difficult so finally I decided to use the data given.)

\* Build, a convolution neural network in Keras that predicts steering angles from images

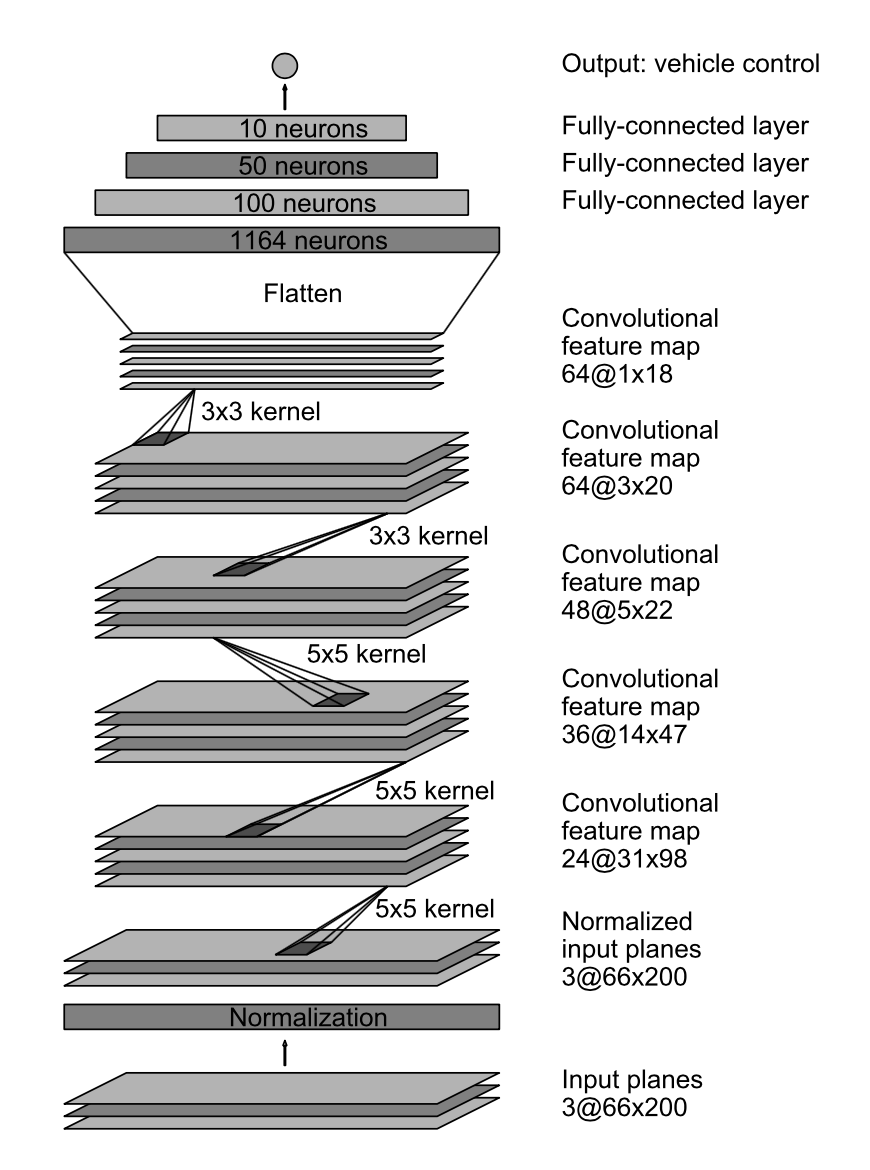
\* Train and validate the model with a training and validation set

\* Test that the model successfully drives around track one without leaving the road

\* Summarize the results with a written report

Model Architecture and Training Strategy

1. Model Architecture



A similar architecture to NVIDA is used. Normalization layer🡪Conv(5,5,24) 🡪MaxPool(2,2)🡪Dropout(0.5)🡪Conv(5,5,36)🡪MaxPool(2,2)🡪Dropout(0.5)🡪Conv(5,5,48)🡪MaxPool(2,2)🡪Dropout(0.5)🡪Conv(3,3,64)🡪MaxPool(2,2)🡪Dropout(0.5)🡪Conv(3,3,64)🡪MaxPool(2,2)🡪Dropout(0.5)🡪RELU🡪Full(240)🡪Dropout🡪RELU🡪Full(120)🡪Dropout🡪RELU🡪Full(20)🡪Dropout🡪RELU🡪Full(1)

The model includes RELU layers to introduce nonlinearity, and the data is normalized in the model using a Keras lambda layer.

1. Attempts to reduce overfitting in the model

The model contains dropout layers in order to reduce overfitting.

The model was trained and validated on different data sets to ensure that the model was not overfitting (0.2). The model was tested by running it through the simulator and ensuring that the vehicle could stay on the track.

1. Model parameter tuning

The model used an adam optimizer, so the learning rate was not tuned manually.

####4. Appropriate training data

Training data was chosen to keep the vehicle driving on the road. I used a combination of center lane driving, recovering from the left and right sides of the road ...

For details about how I created the training data, see the next section.

####3. Creation of the Training Set & Training Process

To capture good driving behavior, I first recorded two laps on track one using center lane driving. Here is an example image of center lane driving:

![alt text][image2]

I then recorded the vehicle recovering from the left side and right sides of the road back to center so that the vehicle would learn to .... These images show what a recovery looks like starting from ... :

![alt text][image3]

![alt text][image4]

![alt text][image5]

Then I repeated this process on track two in order to get more data points.

To augment the data sat, I also flipped images and angles thinking that this would ... For example, here is an image that has then been flipped:

![alt text][image6]

![alt text][image7]

Etc ....

After the collection process, I had X number of data points. I then preprocessed this data by ...

I finally randomly shuffled the data set and put Y% of the data into a validation set.

I used this training data for training the model. The validation set helped determine if the model was over or under fitting. The ideal number of epochs was Z as evidenced by ... I used an adam optimizer so that manually training the learning rate wasn't necessary.