UDACITY

‹ Return to "Self-Driving Car Engineer" in the classroom

DISCUSS ON STUDENT HUB

Finding Lane Lines on the Road

审阅

代码审阅

HISTORY

Meets Specifications

Hello,

Good work overall, you did a good job with your pipeline, Keep this up!
Congratulations, on meeting all of the specifications and good luck with your Self Driving Car Nanodegree. 😄

Required Files

The project submission includes all required files:

- Ipython notebook with code
- A writeup report (either pdf or markdown)

Lane Finding Pipeline

The output video is an annotated version of the input video.

Nice Work, Your videos are properly annotated.

In a rough sense, the left and right lane lines are accurately annotated throughout almost all of the video. Annotations can be segmented or solid lines

Great work here! In the first two videos, there are no intersecting line segments between the left and the right lanes.
Your pipeline is pretty good, with resulting lines right on target.

Visually, the left and right lane lines are accurately annotated by solid lines throughout most of the video.

The left and right lane lines are accurately annotated throughout most of the video. Well done!!

Some improvements might help your annotations work better on the pipeline. Try to implement these recommendations:

- `max_line_gap` that defines the maximum distance between segments that will be connected to a single line.
- `max_line_length` that defines the minimum length of a line that will be created.
- `threshold` increasing will rule out the spurious lines.
- Increasing `min_line_len` and `max_line_gap` for Hough Transform will make your lines longer and will have less number of breaks.(this will make the solid annotated line longer in the output)

Reflection

Reflection describes the current pipeline, identifies its potential shortcomings and suggests possible improvements. There is no minimum length. Writing in English is preferred but you may use any language.

Good work describing your current pipeline and figuring out some of its potential shortcomings and possible improvements.

Whereas more possible improvements are :

- Image from infrared camera.
- Adding a outlier reduction approach like RANSAC on the hough lines.
- Using curve fitting to plot the curve instead of straight lines

For further reference :

RANSAC.pdf
curve.pdf

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