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

Requires Changes

还需满足 1 个要求 变化

This is a good work that meets all the project requirements 👏. Please do go through the comments on your work ✏️. The code looks optimal to me. Keep up the good work that you have put for this project 👍.

This research paper goes into how to detect curves and will also help in detecting faded lanes. It uses an extended version of hough lines algorithm to detect tangents to the curve which can help you detect the curve.
http://airccj.org/CSCP/vol5/csit53211.pdf

The next project goes deeper into handling the challenge video with new computer vision concepts. Happy learning ahead.

Best
Reviewer

Required Files

The project submission includes all required files:

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

The project work meets all the requirements, but I am not sure what your note regarding the draw_lines() function was referring to! Hence marking this as requires changes so that I can clarify the same.

Lane Finding Pipeline

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

there is a clear demarkation between the two lanes! You have taken a very good step towards lane detection and your pipeline reflects that :)

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

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

I would suggest tweaking the following values to get an improvement in lane detection for the first two videos :
threshold ~ 50
min_line_len ~ 100
max_line_gap ~ 160
Increasing the value threshold increases the minimum number of intersection required to detect a line and thus is able to differentiate between the left and right lanes better

min_line_len as the name suggests will help you make sure that the line segments are drawn on the actual lines and thus help eliminate some of the lines.
Increasing your value of max_line_gap will help you get more connected annotated lines when there are broken lanes as it allow points that are farther away from each other to be connected with a single line

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.

重新提交

下载项目

了解 修改和重新提交项目的最佳做法.

返回 PATH

给这次审阅打分