

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.	
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	
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.	
Single solid line ✓ On target ✓	
Screenshot (1194).png	
The left and right lane lines are accurately annotated throughout most of the video. Well done!!	

Your parameters looks good, yet you may try one optimal possible set of parameters which might not create much difference your current output but will be helpful in

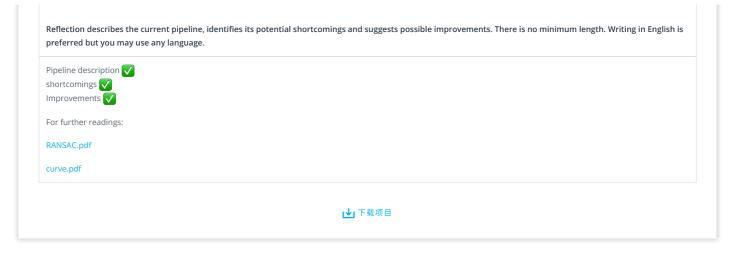
• Decreasing the kernel-size in the Gaussian Filter might also help, as this will remove the noise making the image less blurry.

• Increasing min_line_len (~100 and above) and max_line_gap for Hough Transform will make your lines longer and will have less number of breaks.(this will

Reflection

certain conditions like curved lanes, shadows etc.

make the solid annotated line longer in the output).



返回 PATH

给这次审阅打分