

Lane Detection using Autonomous Car Using Neural Network

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A. *Abstract*— The increase of human desires has pushed the Robo sector to evolve even a lot. One area that begins to bloom in robotic systems are semi-autonomous or autonomous observance and guarding vehicles from a distance. this platform is associate degree example of such a system. it'll be the analysis of its style, construction and operation. The operator driving the vehicle can have video feed and extra data concerning the area monitor. this method may well be the idea of a whole automatic platform with additional sensors will have additional desires. In this paper we will describe the working of Autonomous car which is designed to take its own wise decision upon moving to its destination

II. INTRODUCTION

A. The technology in recent decades developed at a rapid pace, this results to have innovative solutions that facilitate and make human life safer. In particular, the robotics industry has a long term goal of minimizing the manual work carried out every day by people and improving any task that requires human skills such as accuracy, speed and power. Ease of Use Primarily the robotics application fields which caused the biggest development are in the department of robotic arms and small robotic vehicles, which are automated, moving autonomously and transferring information via the Internet or a local network to the central control station. Only in recent years, the field of robotic automatic vehicles has seen the rapid development II

II. *Literature survey*

The problem of road or lane perception may well be an important enabler for advanced driver assistance systems. As such, it's been a full of life field of research for the past twenty years with substantial progress created inside within the past few years. The matter was confronted under varied things, with fully completely different task definitions, leading to usage of numerous sensing modalities and approaches

An formula for detection of marks of road lanes and road boundary by mistreatment intelligent vehicles. It born-again the RGB road scene image into grey image and used the flood-fill formula to label the connected parts of that grey image. at that time the biggest connected element obtained by the formula and that was the road region was extracted. The unwanted region was detected and ablated like outer-side of the road. The extracted connected element was filtered to find white marks of road lane and road boundary. The road lane detection algorithm still had some issues like crucial shadow condition of the image and color of road lanes aside from white.

Lane detection and chase has been an energetic analysis space within the past twenty years in the main for the driving force help application. thanks to the massive variations of traffic scenes and illumination conditions, this downside causes the usage of various approaches and sensing modalities. during this paper, we have a tendency toreview the vision-based lane detection and chase strategies complemented with different sensing element info once necessary. Approaches that adopt standard pc vision techniques square measure reviewed and compared per the separate purposeful modules during a generic framework. information. the colour road image was measure into a binary image. The changed Hough remodel with road pure mathematics consideration was wont to find the lane markings. The bar chart of intensities was applied to quantize the road image into a binary image. A changed Hough remodel methodology has been developed to find thelane markings in road image by using the road pure mathematics info. it absolutely was time overwhelming as a result of Hough remodel was a full search formula in parameter house. It conjointly unsuccessful once the lane boundaries intersected during a region that was a non-road half. The task of finding the pedestrian lanes that square measure indicated by painted markers for the

vision impaired individuals. Associate in Nursing helpful navigation system has been developed for the blind by using geometric figures like line, parabola, or conic. By combining color and native intensity info, this methodology detected properly pedestrian marked lanes in numerous illumination and atmospheric condition (sunny, cloudy, sturdy shadows, times of day)

The technologies employed in such autonomous vehicles areas specific in a additional mature stage, however due to the advanced interaction between them, there is still a lot of development to be done in engineering at the field of connecting all subsystems that integrated end system can operate autonomously in advanced environment.

III. BLOCK DIAGRAM

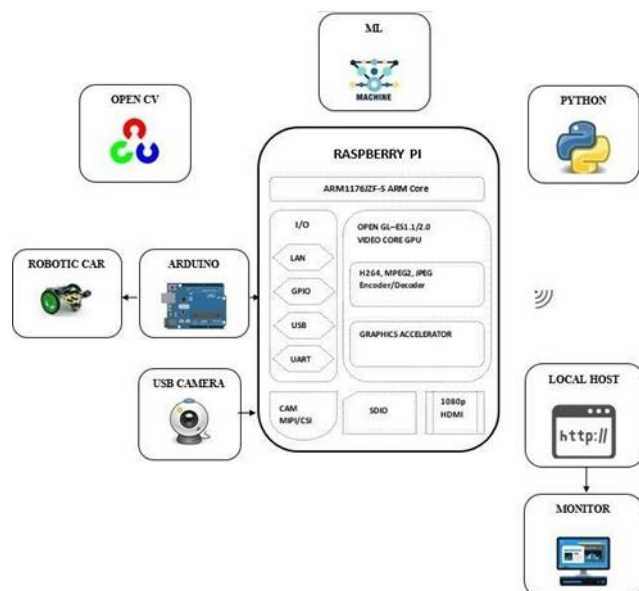


Fig 1 Hardware Components



Fig 2 Ultrasonic Sensor

A. *List OF HardWare*

- Raspberry Pi
- Ultrasonic Sensors
- Dc Motors
- D.C. Power Supply
- Arduino

B. *Raspberry pi*

The RPi3 has new quad 64bit ARM-type processor core clocking 1.2GHz, which can be increased (overclocking). The features and only the processor give very high computational power in order to widen the range of software which can be used and the confidence that the system is stable, no ups and downs on its performance. Also, four of our CPU cores give the ability to have multiple functions simultaneously active. The computer has 1GB RAM, which speeds up data processing. One of the features that stand out from the rest of the class is the built-in Wi-Fi. Also for the connection with other devices and is integrated Bluetooth Low Energy (BLE). Moreover, a CSI port is available for connecting the camera. software in operating scenarios and informing the user. In particular, the user in one of the auxiliary operating scenarios can move the distance sensor LIDAR Lite to receive distance data barriers.

C. *UltraSonic Sensor*

The sensors are devices that convert some events or physical quantities into electrical signal so as to form the measurement. The sensory organs (robotic sensor)the automaton the flexibility to spot and detects that it is additional like human behavior. External Sensors contract with the observation of the environmental options on thatthe robotic vehicle is moving, such as wetness or the colors of associate object. The external sensors that activate with the touch of an object known as contact sensors, and every one the remainder, because the sensory systems supported camera, known as non-

contact sensors, and mimic human eyes, see

D. **MicroController** : The microcontroller used in the present construction is Romeo BLE. The specific microcontroller is based on Arduino UNO, has additional guidebook motor (Motor Driver) and built-in Bluetooth 4.0. It is designed specifically for robotic applications. The Romeo benefit from the open source Arduino platform is supported by thousands of open source projects, and can be easily extended with Arduino Shields. Apart from DC motor can lead stepper motors and servo motors. The Romeo BLE behaves like Arduino UNO based on ATmega328P chip. It can be programmed via the Arduino IDE environment, something which greatly facilitates the code development process. Also there are plenty of libraries that can be used to develop applications. The objective of this platform is the movement of the space by remote control and monitoring. That is because it was not sufficient to implement only the microcontroller.i

E. *Software hardware-specific requirement*

A Raspb Pi which is , connected with a pi camera module associated an inaudible device and is employed that is hc- sr04 to gather computer file.Raspberrypi runs two Consumerprograms for color streaming video and ultrasonic device knowledge to the pc via native Wi-Fi affiliation. In order to achieve video streaming on low latency, is scaled allthe way down to QVGA

(320*240) video resolution technique to notice so straight lane boundaries can be tracked, employing a progressive single camera mounted on-board. the tactic established to be strong, even under varied lighting conditions, and within the presence of serious shadowing solid by vegetation, vehicles, bridges, etc. Moreover, false positive hardly occur. The lane markings ar being endlessly detected even once the vehicle isactivity maneuvers like excursion or lane amendment.

Detection victimisation stereo camera for self driving automobile. once vehicles ar exist on the road, it's troublesome to seek out load sign like lane, crosswalk, stopline, etc.

G. *Implementation*



Fig:3 RC Car

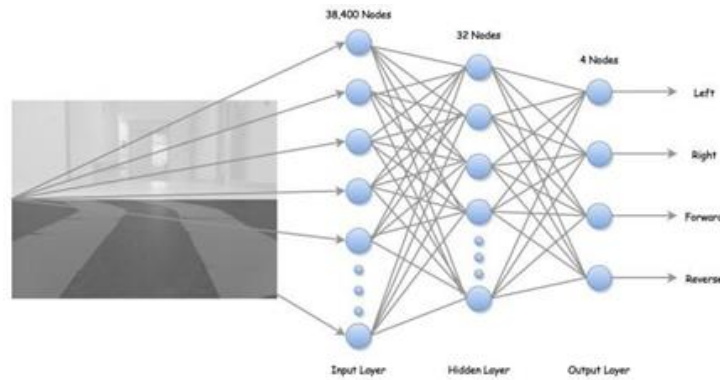


Fig:4 Neural Network Data Nodes



Fig:5 Cascade Filters

F. Neural Network

Constructing neural network is that once the network is trained it has the advantage to fully load trained parameters when, there is no time for prediction. fully lower 1/2 the input image is utilized for Train and prediction functions.

There unit thirty eight,400 (320120) nodes at intervals the input layer and thirty 2 nodes of hidden layer at intervals. the quantity of the hidden layer are the nodes which are at intervals are chosen fairly impulsive. The intervals of the output layer unit which has four nodes each node corresponds to the steering instructions are: forward, right, left and reverse severally (its still fenced at intervals of the output layer though reverse isn't used anywhere throughout this project). Initial each frame is cropped and converted to a numpy array. Below shows the information assortment technique. The information is paired to train with labels then the train images which is (human input). Finally, in a npz file all paired image with information and labels units are saved in file. In OpenCV the neural network is trained with the method called pattern back propagation methodology. therefore eight units saved into a xml file Once its trained and is completed, Constant neural network will be created

to duplicate with predictions, and loaded it with trained Xml This project is custom-made approach and used Har feature-based cascade classifiers with the shape-based for object detection. Coaching and detection is a similar method used Since every object needs its own classifier and follows in fig, this project targets solely on stop sign signal detection and traffic signals A) To observe the stoplight, trained classifier cascade is employed . As a district of interest (ROI) is considered AS The bounding box. Secondly, Within the ROI (Rate of interest) Gaussian blur will be applied

for Noise reduction. Thirdly, realize that the red or inexperienced states is the brightest purpose within the ROI. Finally, the position of the brightest spot within the ROI are determined supported

merely

B) A camera module which is solely supported by Raspberry Pi. the RC automobile additionally appears unpractical Using the two USB internet cameras that can bring further weight to Rc car. Therefore, visual modality methodology is chose..

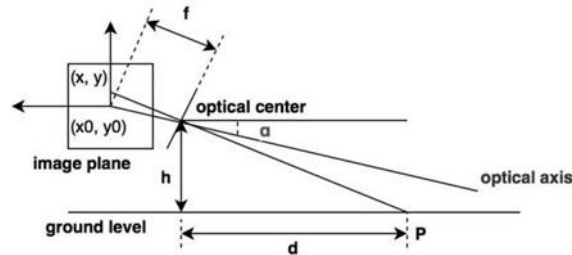


Fig:6 Geometry to describe the camera on top of car the aim on the target object is P ; the distance from

optical center is d, and to the purpose P . supported the relation of math , formula (1) shows the distance d. within the formula (1) , f is that the focal distance of the camera to calculate; the camera is at tilt angle; h which is height of optical center ; intersection purpose of image plane and optical axis (x0, y0) refers to the (x, y) projection of the image plane which is purpose P . Suppose O1 (u0,v0) is intersection of optical axis and image plane of the camera coordinate , conjointly the Dimension of physical picture element admire axis and axis on the plane image measured square metal and dx. Then::

$$d = h / \tan (\theta + \arctan ((y - y_0) / f)) \quad (1)$$

$$u = \frac{x}{dx} + u_0 \quad v = \frac{y}{dy} + v_0 \quad (2)$$

Let $x_0 = y_0 = 0$, from (1) and (2):

$$d = h / \tan (\alpha + \arctan ((v - v_0) / a_y)), \quad (a_y = f / dy) \quad (3)$$

Fig:5 Mathematical Formula

RC CAR UNIT:

H. The project has degree RC automotive used throughout switch kind of controller which is on/off .It has the resistance between the relevant chip pin and once a button is sleek and ground is 0. Thus, the button-press actions is used to simulate degree of Arduino board . The four chip pins on the controller which has Four Arduino pins to connect to unit area opt , like to reverse, forward, right and left with corresponding actions. The pin chip of the controller inflicts low signal that indicates grounding in Arduino pins ; among pins chip and keeps ground unchanged indicate inflicting High signal which indicates resistance. The USB which is connected to the computer through Arduino. the serial interface is practice through Arduino in which the system outputs command , such that the the commands and gives out high or low signals is read by the arduino

, the RC automotive drive with actions when the buttonis pressed

I. Results and Discussion



Fig:6 Measure stop Signal within Distance The testing samples returns Associate in the accuracy of eighty five Prediction on % associated with the accuracy ofthe coaching samples that returns 96 % . The calculations square that measures In actual driving scenario, 10 times a second with generated concern (streaming rate roughly ten frames/s). rotation sensitive measure Haar square nature by options . during this project, however, rotation isn't a apprehension as each the mounted objects, measure square stop sign and therefore the stoplight in general case that's in addition real world setting sensing element, surface condition and sensing angle into concerns. On the opposite hand, “good enough” activity provides results Pi camera. In fact, the particular distance as we all know the corresponding number as long as the data is , The Experimenting

results of sensing distance through pi. is to prevent the RCar automobile

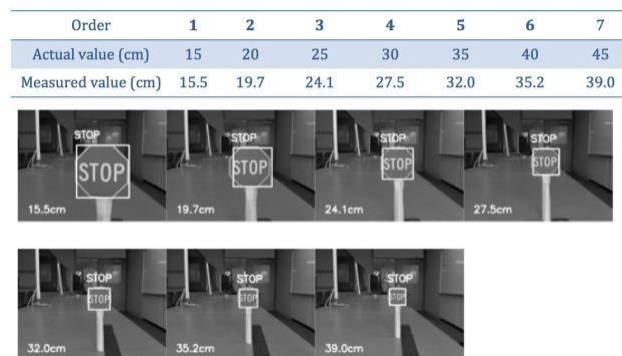


Fig:8 Camera Measure to detect stop sign using Opencv

lane detection using autonomous car usingneural network

In this project, the distance measure victimization light- weight visual modality approachaccuracy that by the subsequent factor that could be influenced (1) actual value of measure has errors in , object bounding box in police work method which has variations , (3)activity method that has errors privately,(4) it has nonlinear relationship between cameracoordinate and distance , the RC car may with success with the navigate particle has the errors that are bigger

Type	Number of positive sample	Number of negative sample	Sample size (pixels)
Stop sign	20	400	25x25
Traffic light	26	400	25x45

Fig:9 Approximation for Detection



Fig:7 Measure stop Signal within Distance

The degree obstacle associate ahead of the RC automotive and provides results that are correct For measuring the distance features, the verify the distance that once taking,

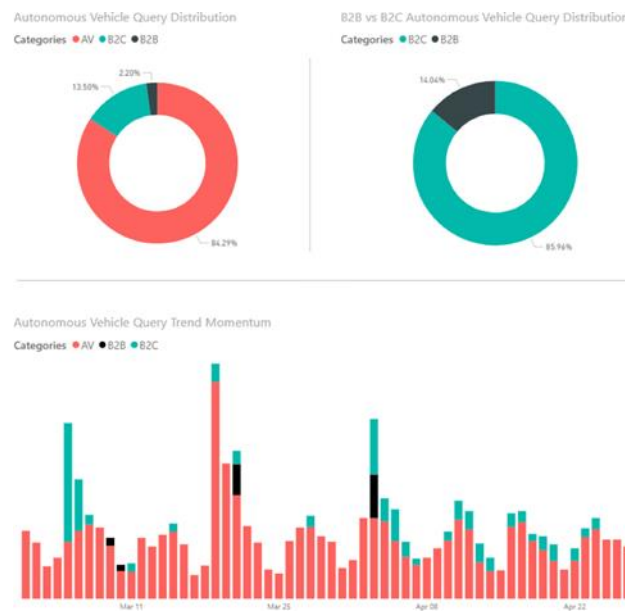


Fig Observation

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