

Real-time End-to-End Lane ID Estimation Using Recurrent Networks

Ibrahim Halfaoui, Fahd Bouzaraa, Onay Urfalioglu

LiMinzhen

Huawei Technologies Duesseldorf GmbH Munich, Germany Huawei Intelligent Automotive Solution BU Shanghai, China

I. Introduction:

- •Task description: Given a visual representation of a driving scene (image), the car should be able to identify which lane it is driving on.
- The identification is defined by a number/Identifier of the lane (Lane ID estimation).





3. Pre-processing:

- we track the average perceived brightness of the driving sequence given as input.
- ➢ If the perceived brightness of the current frame is below the tracked average → Adjust the brightness of the frame.
- The brightness adjustment can be done via a linear transformation of the pixel intensities (with a corresponding alpha parameter).

 $R'(x, y) = \min(255, \alpha . R(x, y))$ $G'(x, y) = \min(255, \alpha . G(x, y))$ $B'(x, y) = \min(255, \alpha . B(x, y))$

4. Loss Function:

II. Method:

1. Dual Convention:

For our end-to-end approach, we are using a Dual ID
Convention:



$\delta \mathbf{l} + \delta r + \mathbf{1} = C$

In this case, the car is on:

- $\delta \mathbf{l} = \mathbf{3}$ from left.

- $\delta r = 1$ from right.

- C = 5 is total lane count.

Classification task N = 8 with a proposed cost function is composed of 3 parts:

- Cross Entropy Loss
- Adaptive Penalty
- Triangular Regularization
- L_gt: Ground Truth LEFT Lane ID
- R_gt: Ground Truth RIGHT lane ID 1 +
- C_gt: Ground Truth LANE count
- L: Estimated LEFT Lane ID
- R: Estimated RIGHT lane ID
- C: Estimated LANE count

III. Results:









2. Model:



Closed-Loop Design using LSTMs (Long-Short-Time-Memory)

An Encoder-decoder Model with interposed Conv-LSTM cells between

the layers to get profit from temporal dimension \rightarrow Moka-convLSTM

