

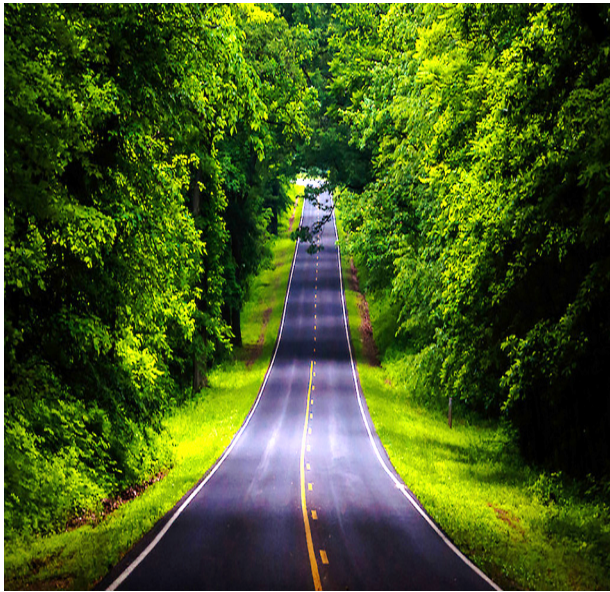
A photograph of a dark, wet asphalt road with several potholes. The road is flanked by dark, dense foliage. The text "Pothole Detection And Visualization" is overlaid in the center in a bold, yellow font.

Pothole Detection And Visualization

About Me

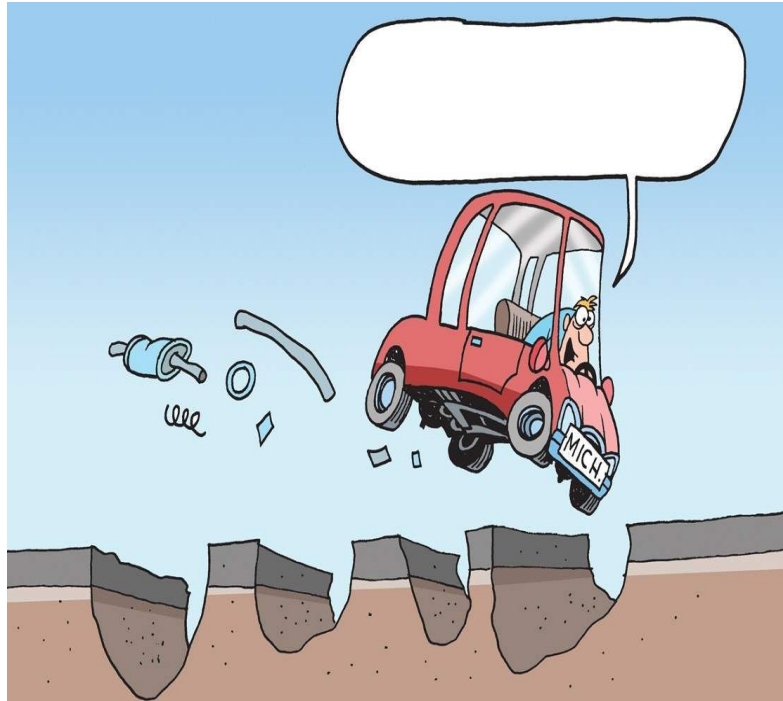
- I am a 3rd year Undergraduate Student at UCET, Bikaner, currently known as Bikaner Technical University(BTU).
- I am pursuing my B.Tech degree in Computer Science and Engineering.
- Skills
 - Deep Learning
 - Artificial Neural Network
 - Machine Learning
 - Data Science
 - GUI with Python and Java

Kind of Roads we Like



Kind of Roads we Hate

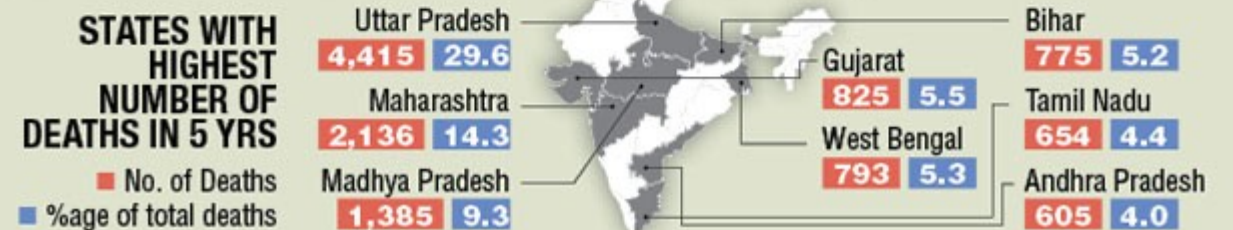
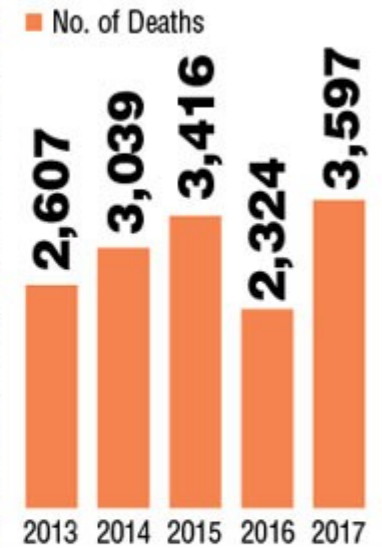
Road Accidents due to Potholes





DEADLY POTHOLES OF THE COUNTRY

ROAD ACCIDENT DEATHS MORE THAN FATALITIES CAUSED BY TERRORIST ATTACKS IN INDIA

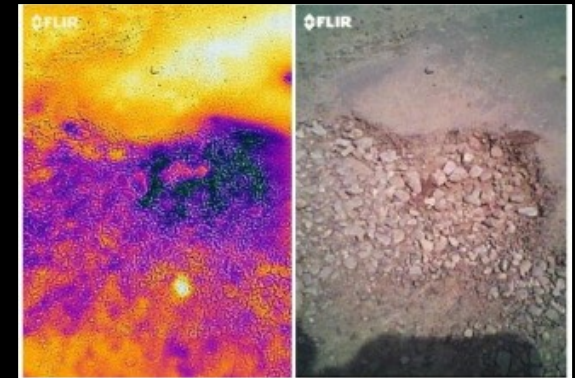
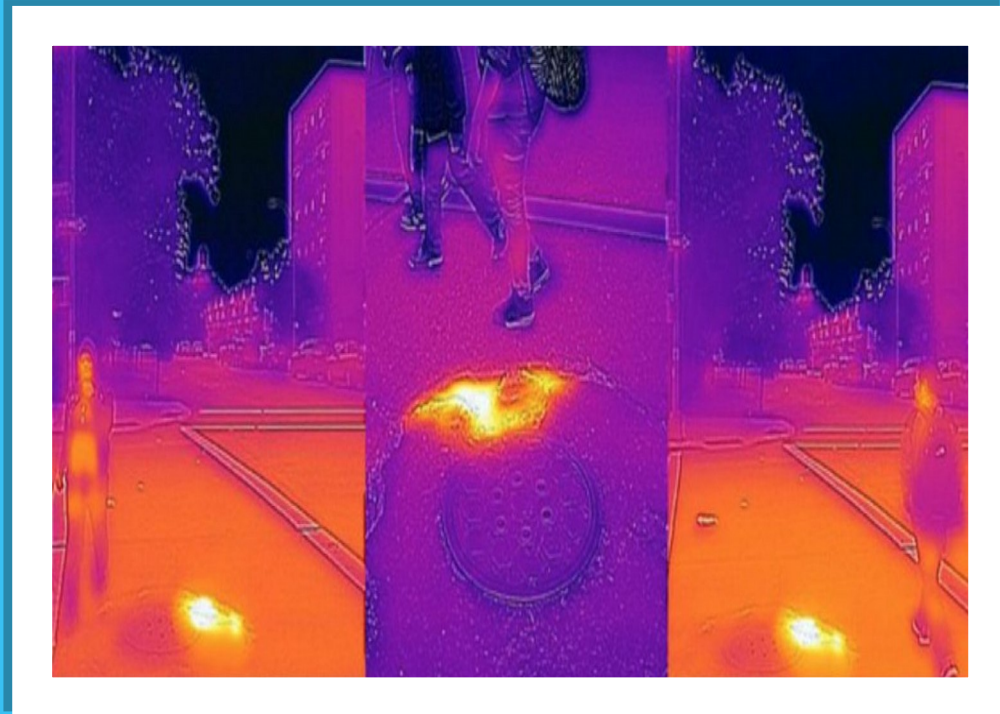


Techniques for Pothole Detection

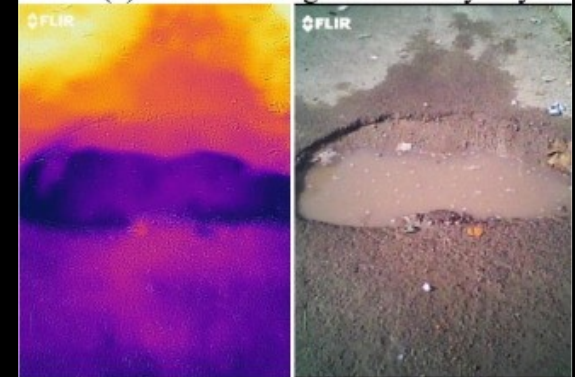
Mainly there are three main techniques:-

- Thermal Imaging
- Image Processing and CNN
- Sensor Detection

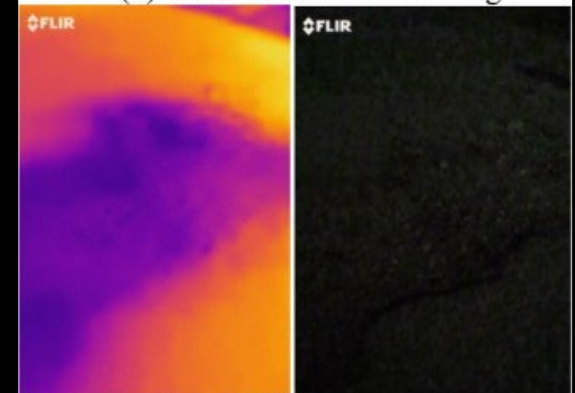
1. Thermal Imaging



(a) Pothole image on a sunny day



(b) Water-filled Pothole image

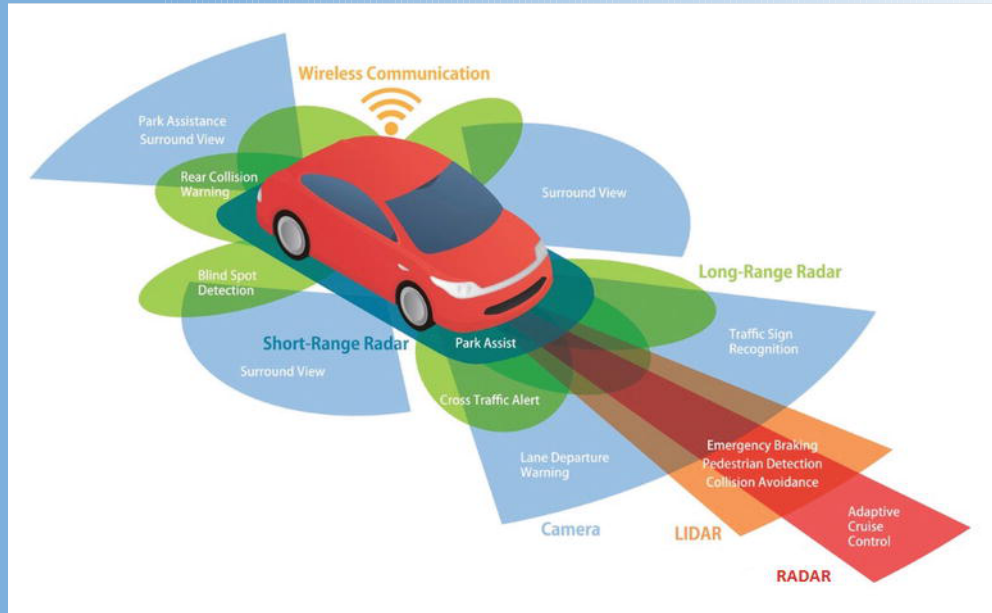


(c) Pothole image at night

2. Image Processing and CNN



3. Sensor Detection



POTHOLE ALERT RESEARCH

Jaguar Land Rover is researching a new connected car technology that will allow a vehicle to identify the location and severity of potholes, broken drains and manhole covers. It will then share this data in real time with other vehicles and with road authorities to help them prioritise repairs.

The diagram shows a red Range Rover SUV on a road. Blue sensor waves emanate from the front of the car, scanning the road ahead. A pothole is visible on the road surface. A camera in the front windscreen is shown taking an image of the pothole. The car is connected to 'The Cloud' via a dashed orange line. A legend indicates that the camera can take an image of the pothole and that the car can scan the road ahead. A 'Pothole' is also labeled on the road surface.

Camera (in front windscreen) could take an image of the pothole

The Cloud

ALERT - POTHOLE

RECORDING DATA FROM CLOUD

EMERGENCY COMPLETE

POTHOLE DETECTOR

CARTOGRAPHIC

LATITUDE: 55.279363

LONGITUDE: -1.504114

Pothole

Car could also scan the road ahead

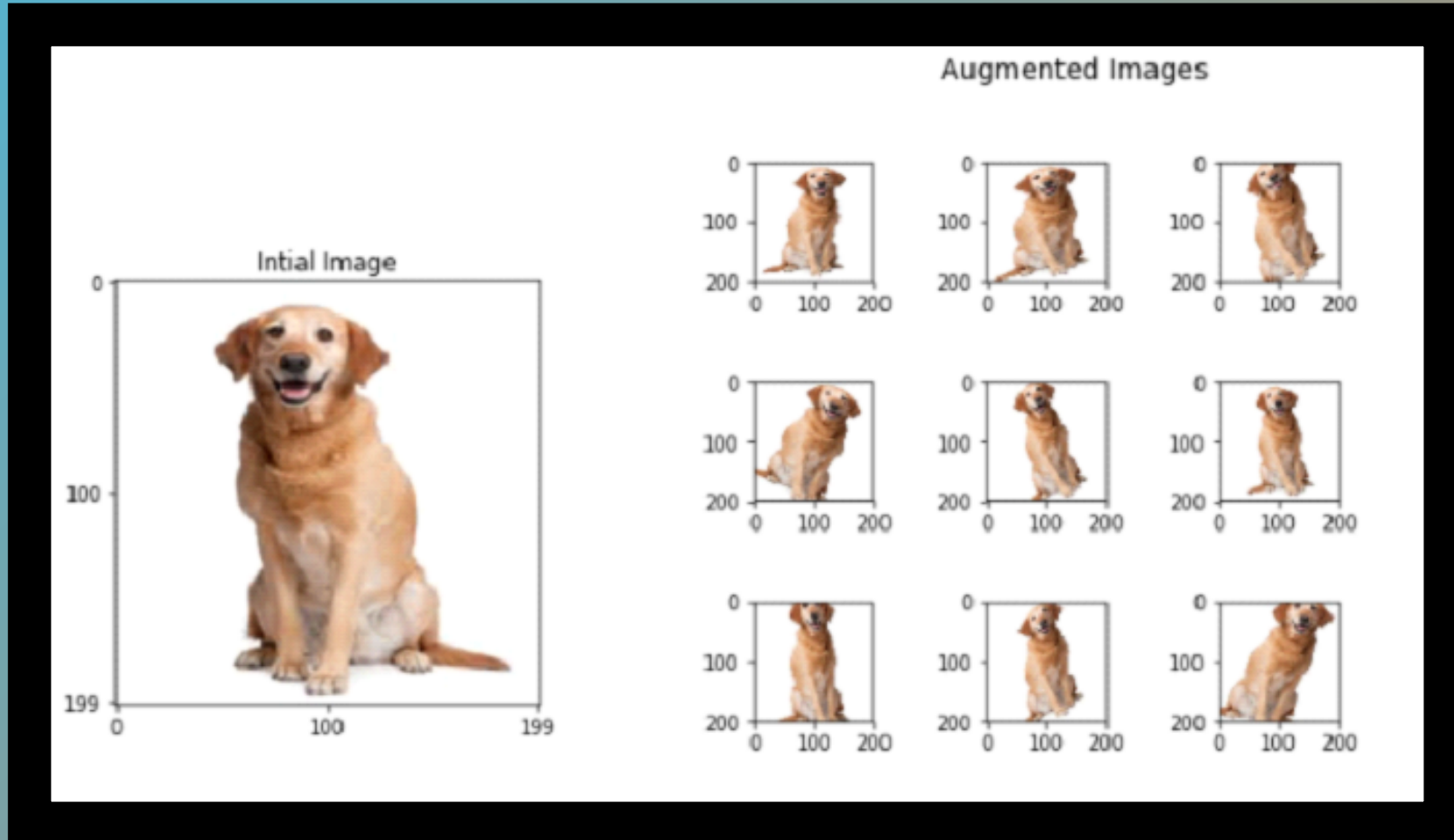
Data also shared with roads authorities, together with GPS location, to aid repairs

JAGUAR LAND-ROVER

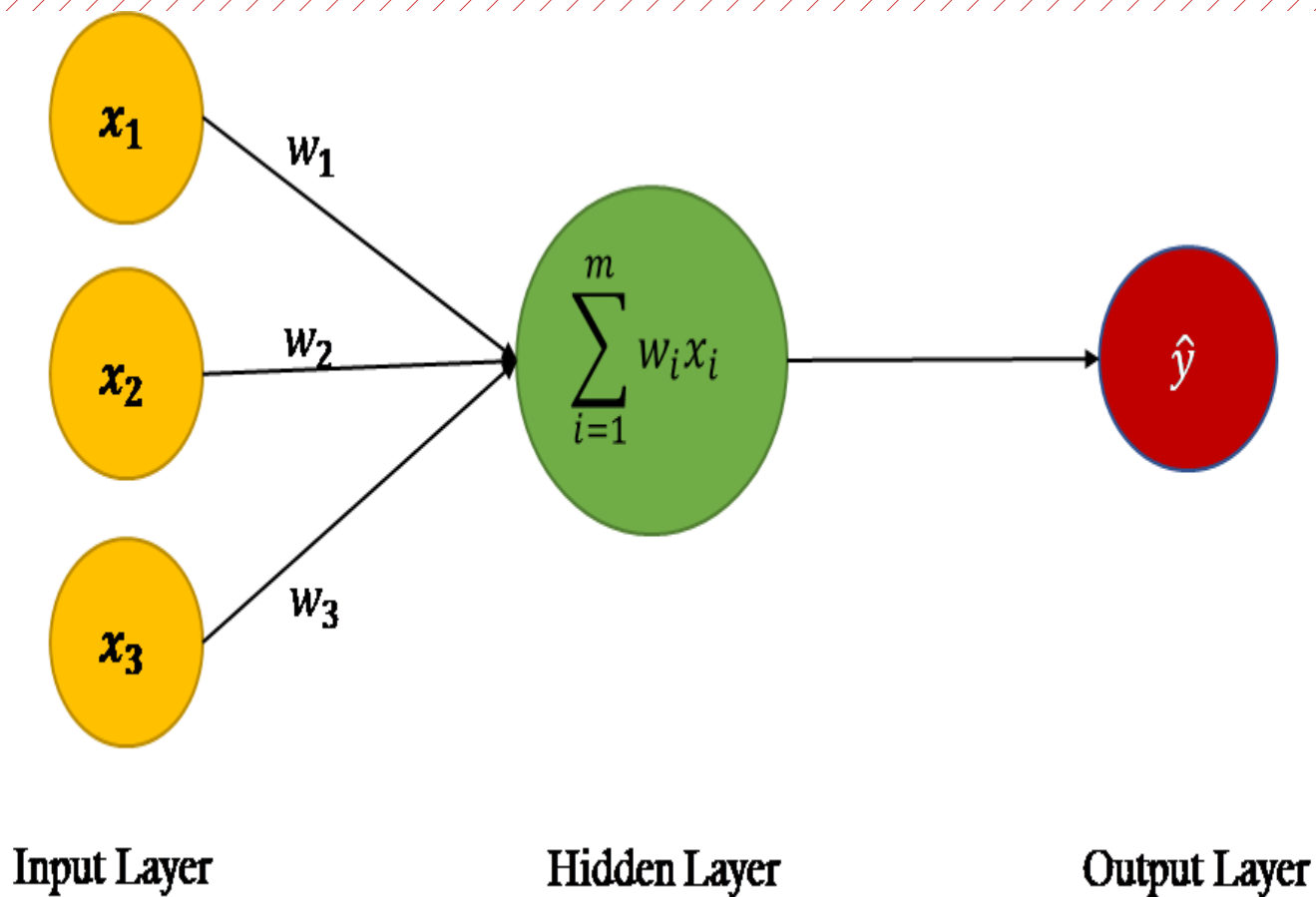
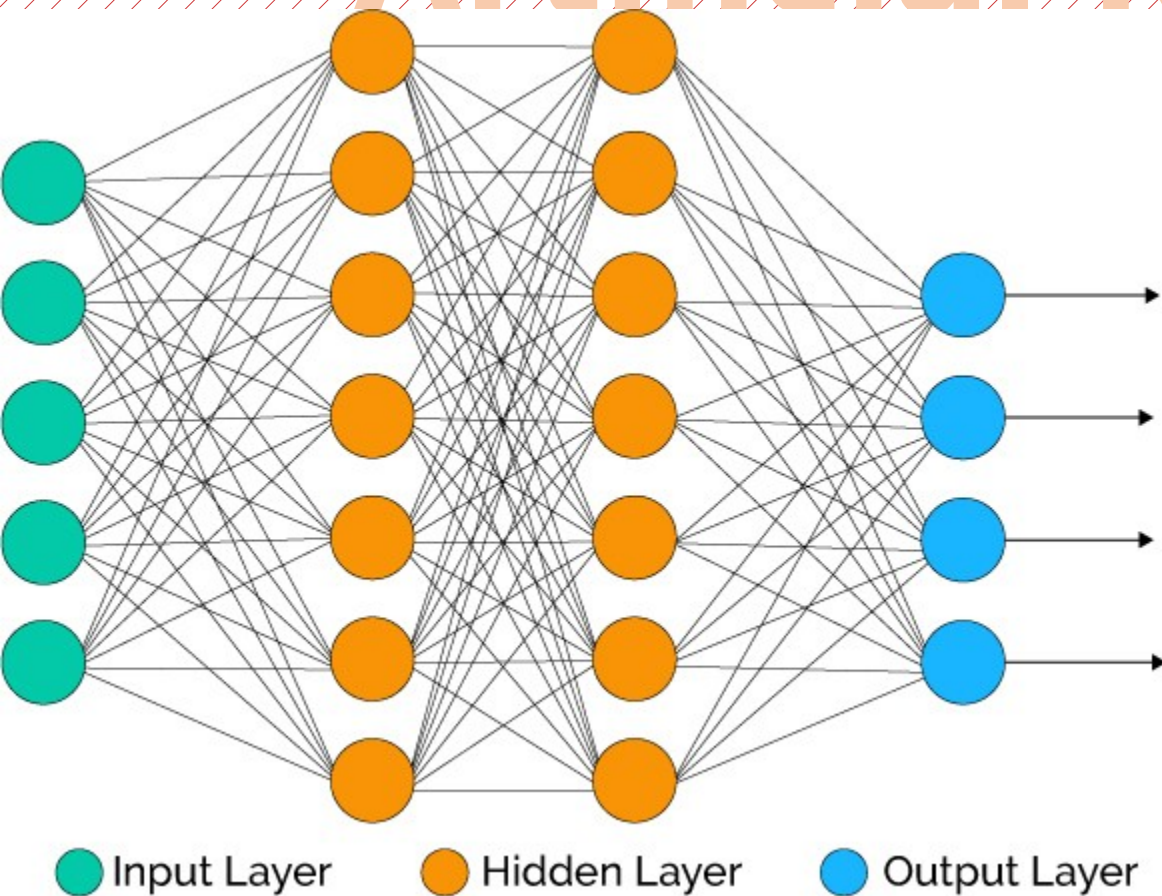
Any Incident that
Triggered this idea



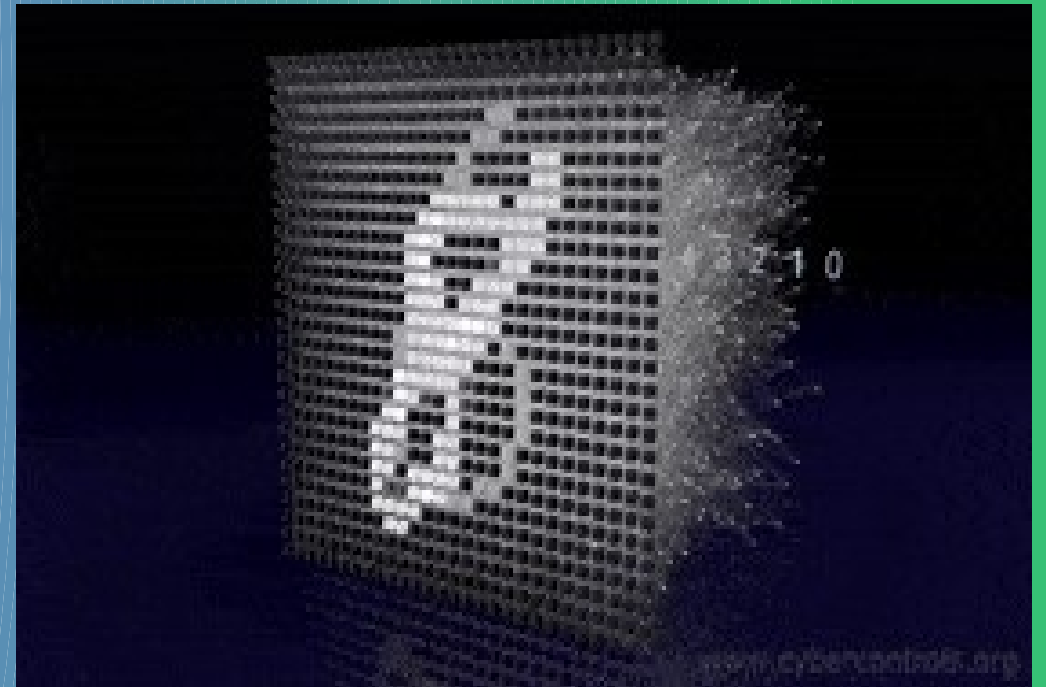
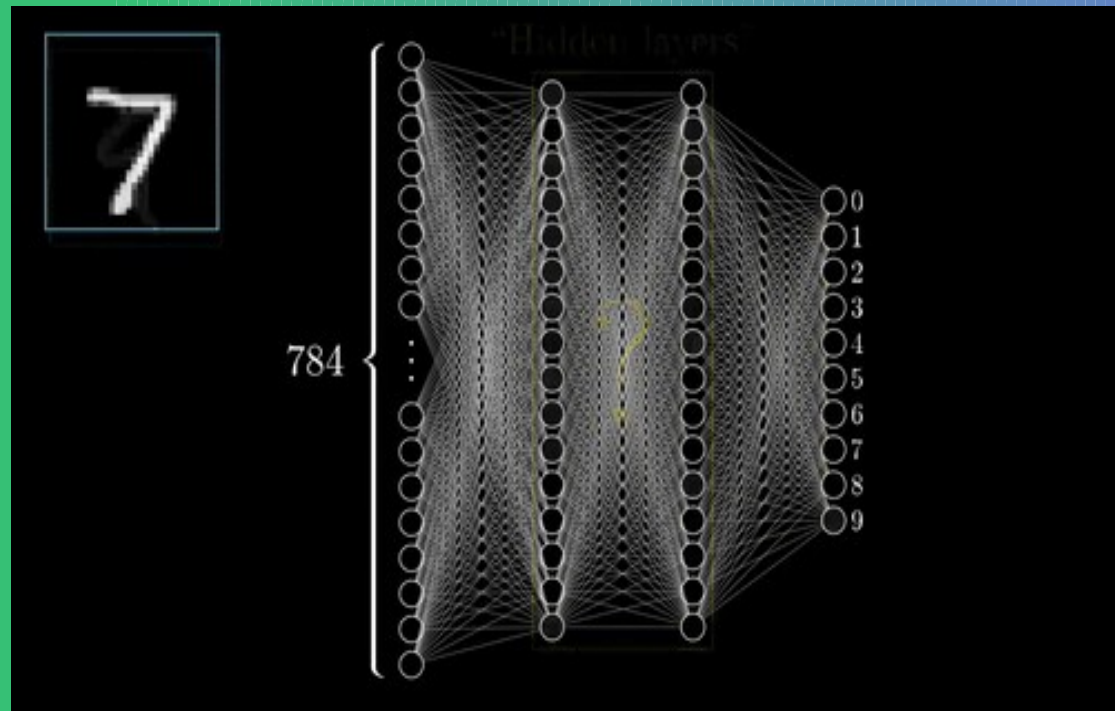
Image Augmentation



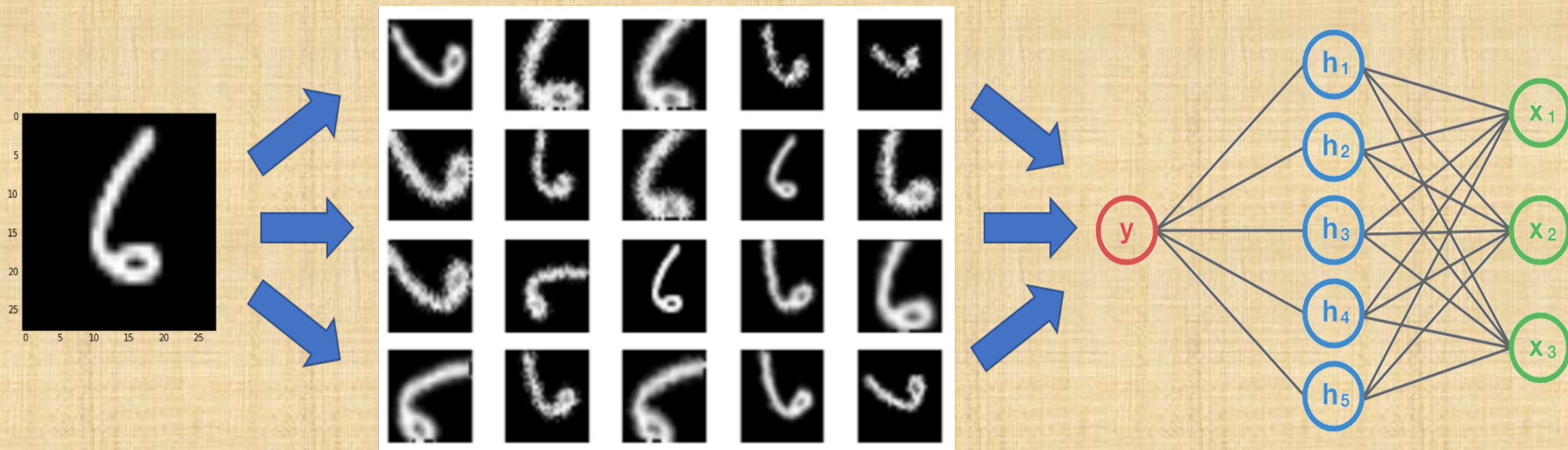
Artificial Neural Network



Convolutional Neural Network



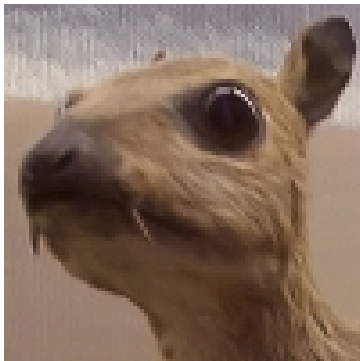
Working:



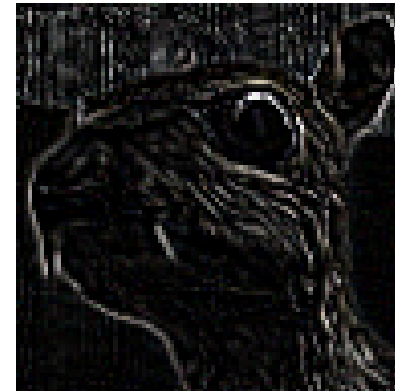
Kernel

- In image processing, a **kernel**, **convolution matrix**, or **mask** is a small matrix. It is used for blurring, sharpening, embossing, edge detection, and more. This is accomplished by doing a convolution between a kernel and an image.
- The general expression of a convolution is:

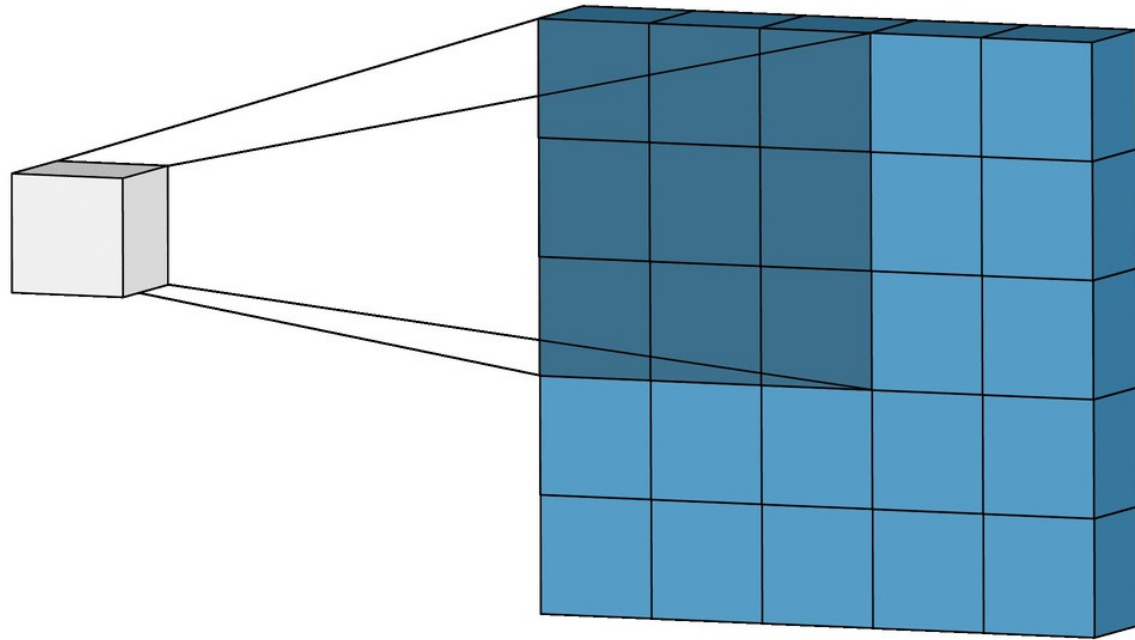
$$g(x,y) = w * f(x,y)$$



-1	-1	-1
-1	8	-1
-1	-1	-1



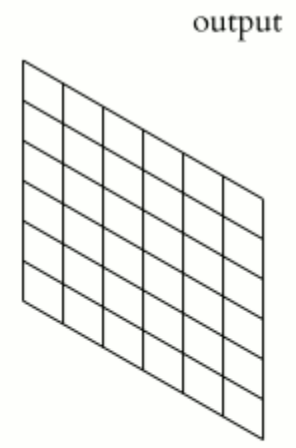
Convolutional 2D



7	6	5	5	6	7
6	4	3	3	4	6
5	3	2	2	3	5
6	4	3	3	4	5
7	6	5	5	6	7

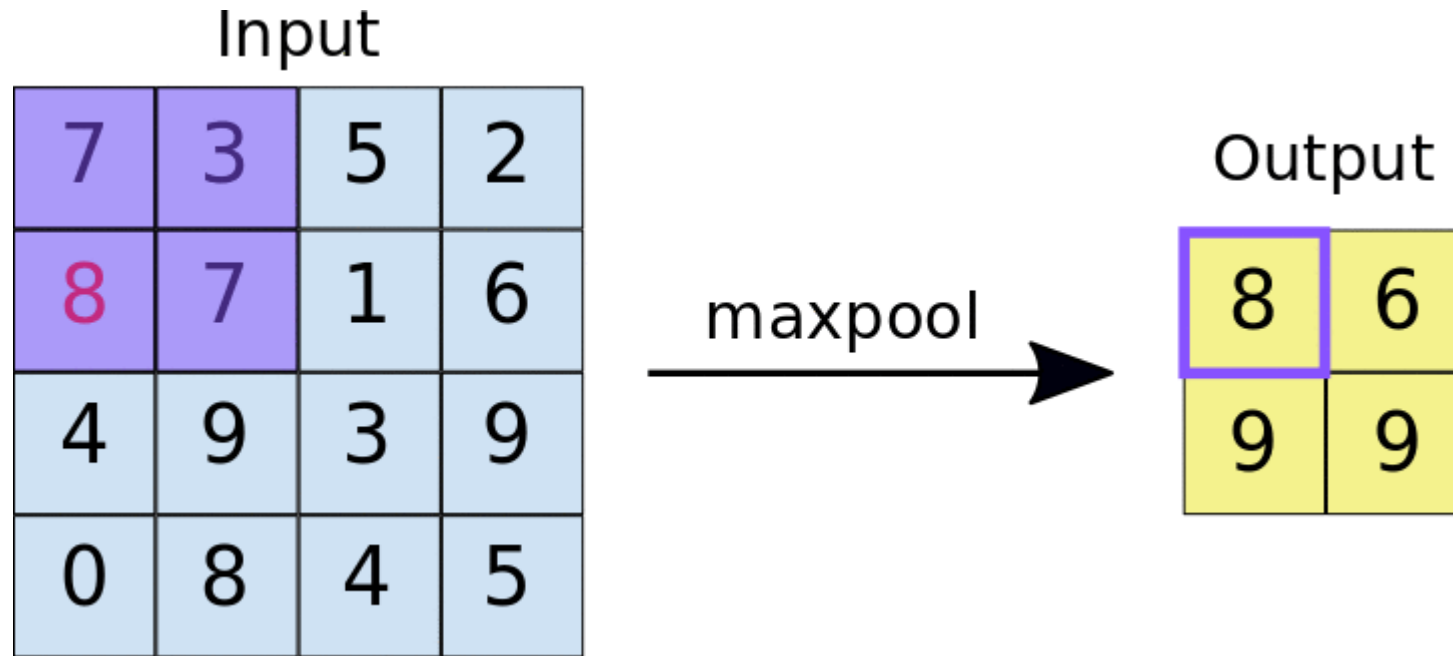
0	-1	0
-1	5	-1
0	-1	0

input

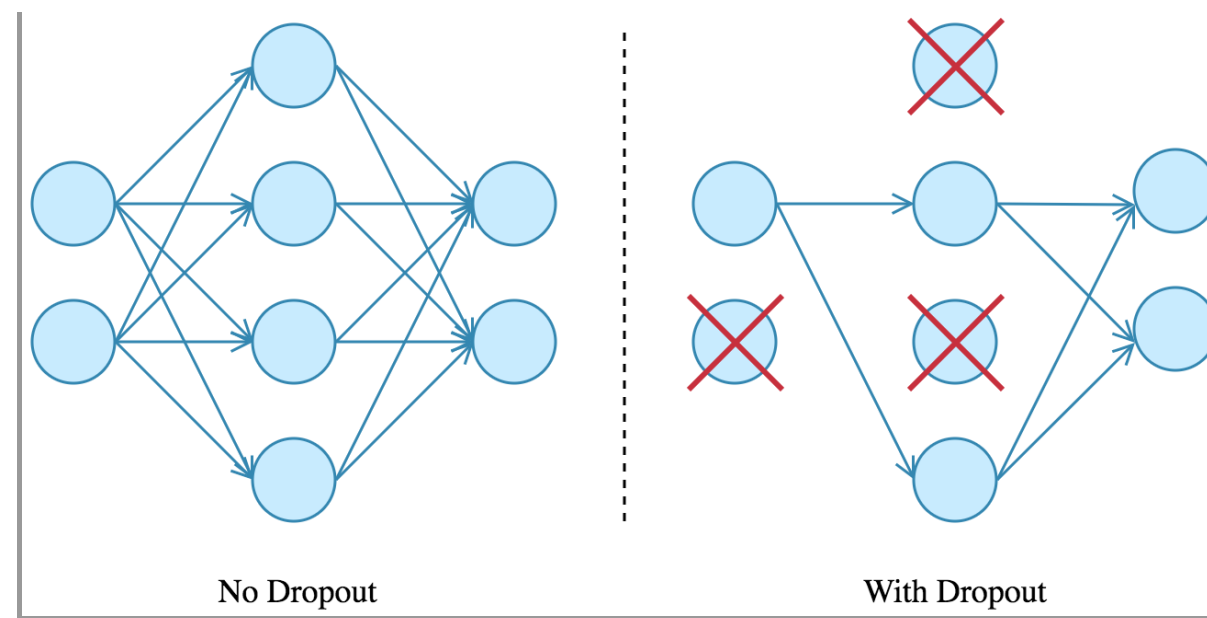
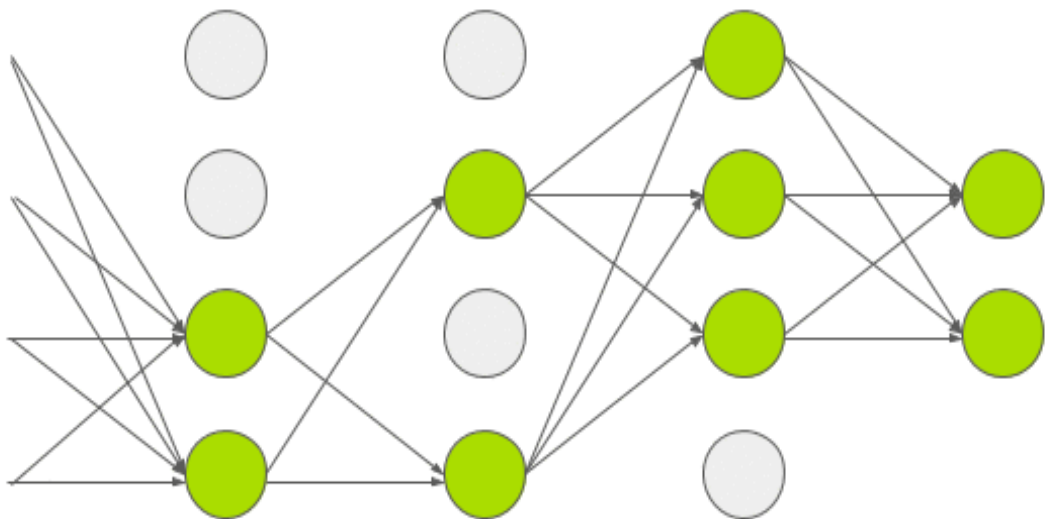


output

MaxPooling



Dropout

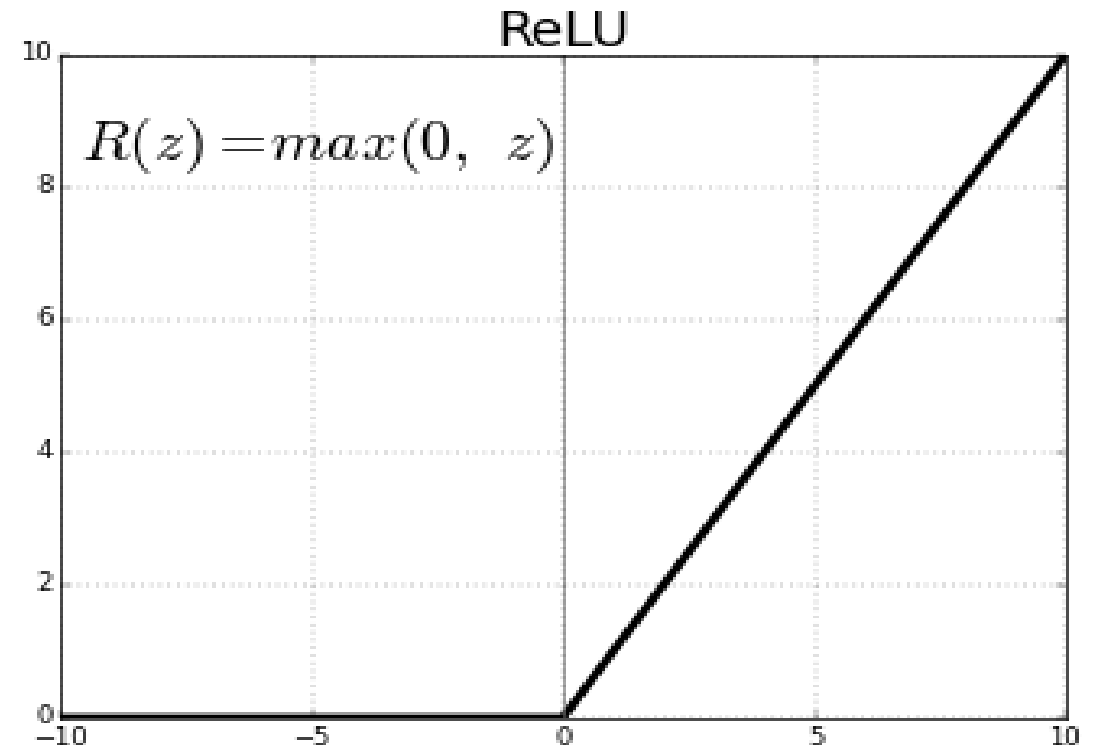
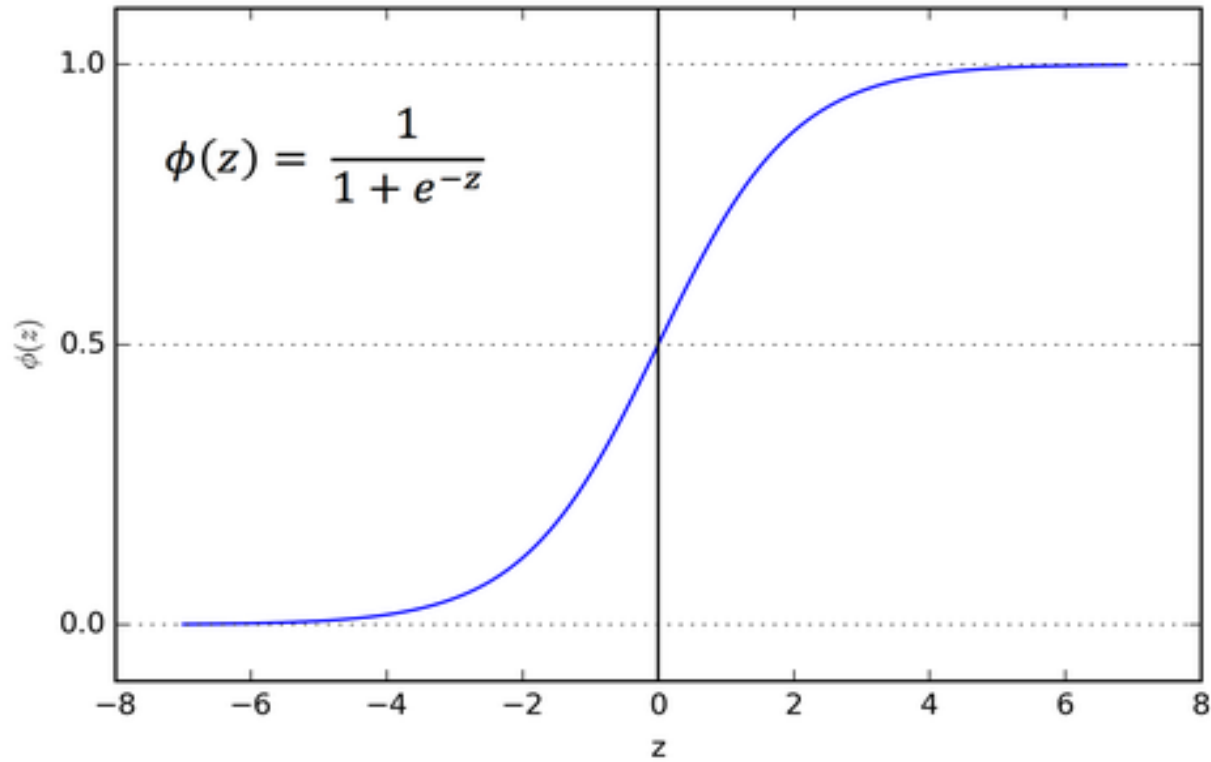


Activation Function

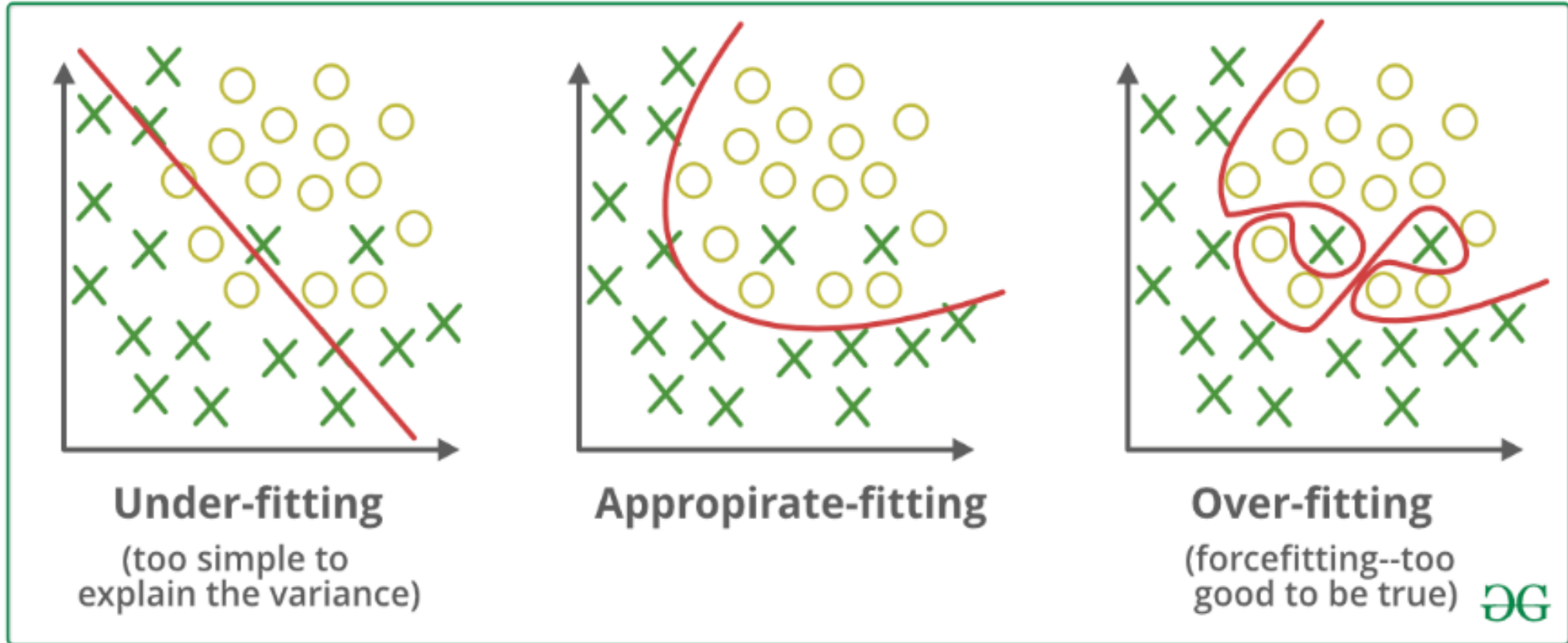
- The activation function is the non linear transformation that we do over the input signal. This transformed output is then sent to the next layer of neurons as input.
- Names of Activation Function:
 - ❖ Sigmoid Function
 - ❖ Tanh Function
 - ❖ ReLU Function
 - ❖ Leaky ReLU Function
 - ❖ Maxout Function
 - ❖ ELU Function
 - ❖ Softmax Function

Sigmoid Function Function

ReLU



Overfitting and Underfitting



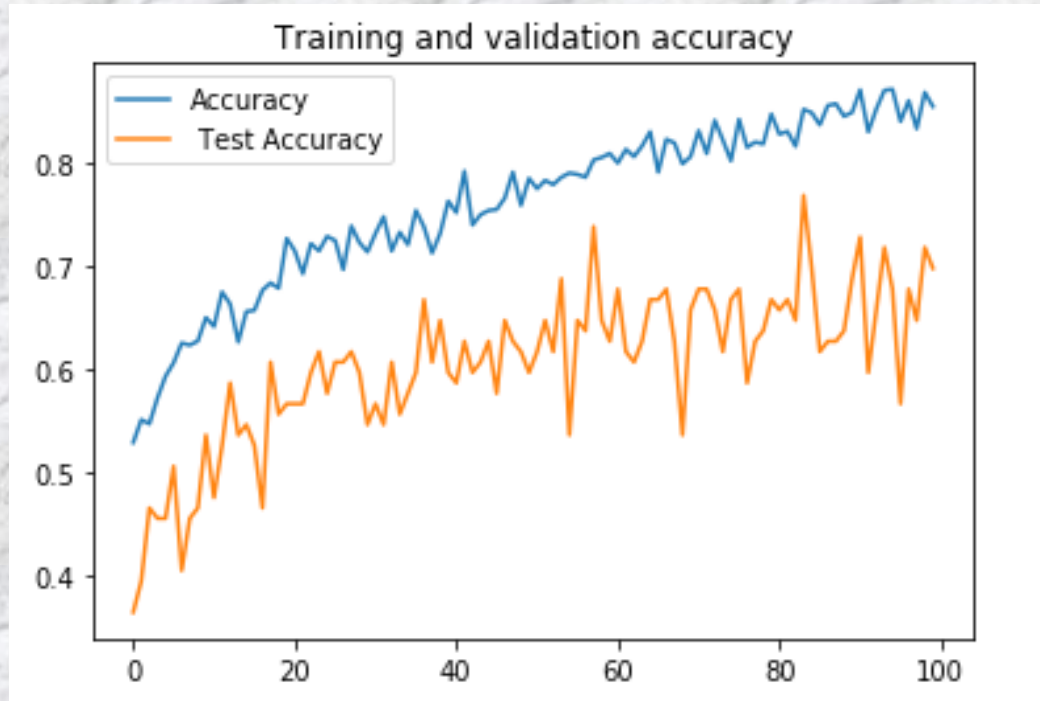
Model Description

Model: "sequential"

Layer (type)	Output Shape	Param #
conv2d (Conv2D)	(None, 238, 238, 16)	448
max_pooling2d (MaxPooling2D)	(None, 119, 119, 16)	0
conv2d_1 (Conv2D)	(None, 117, 117, 32)	4640
max_pooling2d_1 (MaxPooling2D)	(None, 58, 58, 32)	0
conv2d_2 (Conv2D)	(None, 56, 56, 64)	18496
max_pooling2d_2 (MaxPooling2D)	(None, 28, 28, 64)	0
conv2d_3 (Conv2D)	(None, 26, 26, 128)	73856
max_pooling2d_3 (MaxPooling2D)	(None, 13, 13, 128)	0
flatten (Flatten)	(None, 21632)	0
dense (Dense)	(None, 512)	11076096
dropout (Dropout)	(None, 512)	0
dense_1 (Dense)	(None, 1)	513

=====
Total params: 11,174,049
Trainable params: 11,174,049

Performance Curves



Let's talk about Android

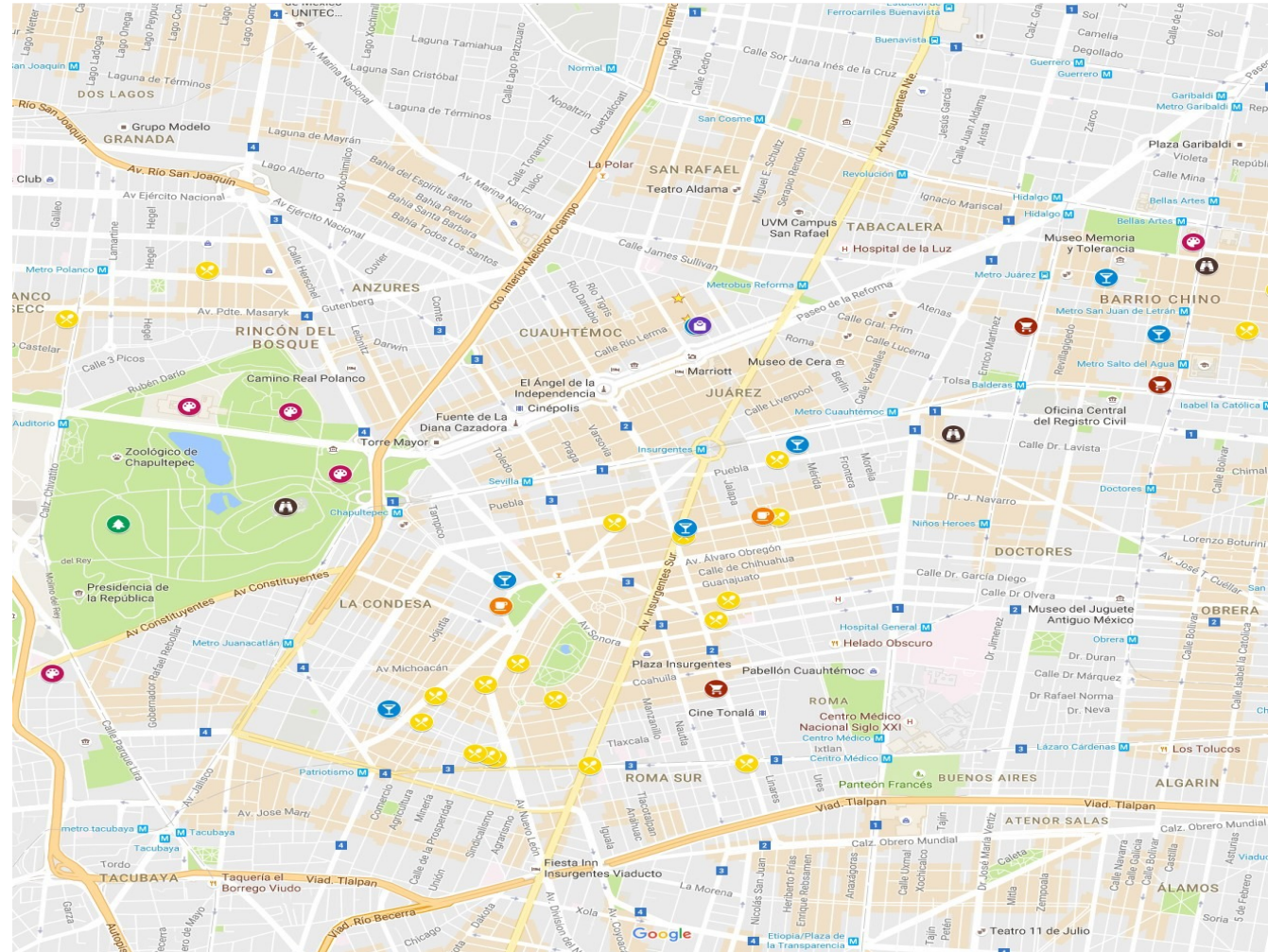
Only A Little

- Google Map API
- Polyline

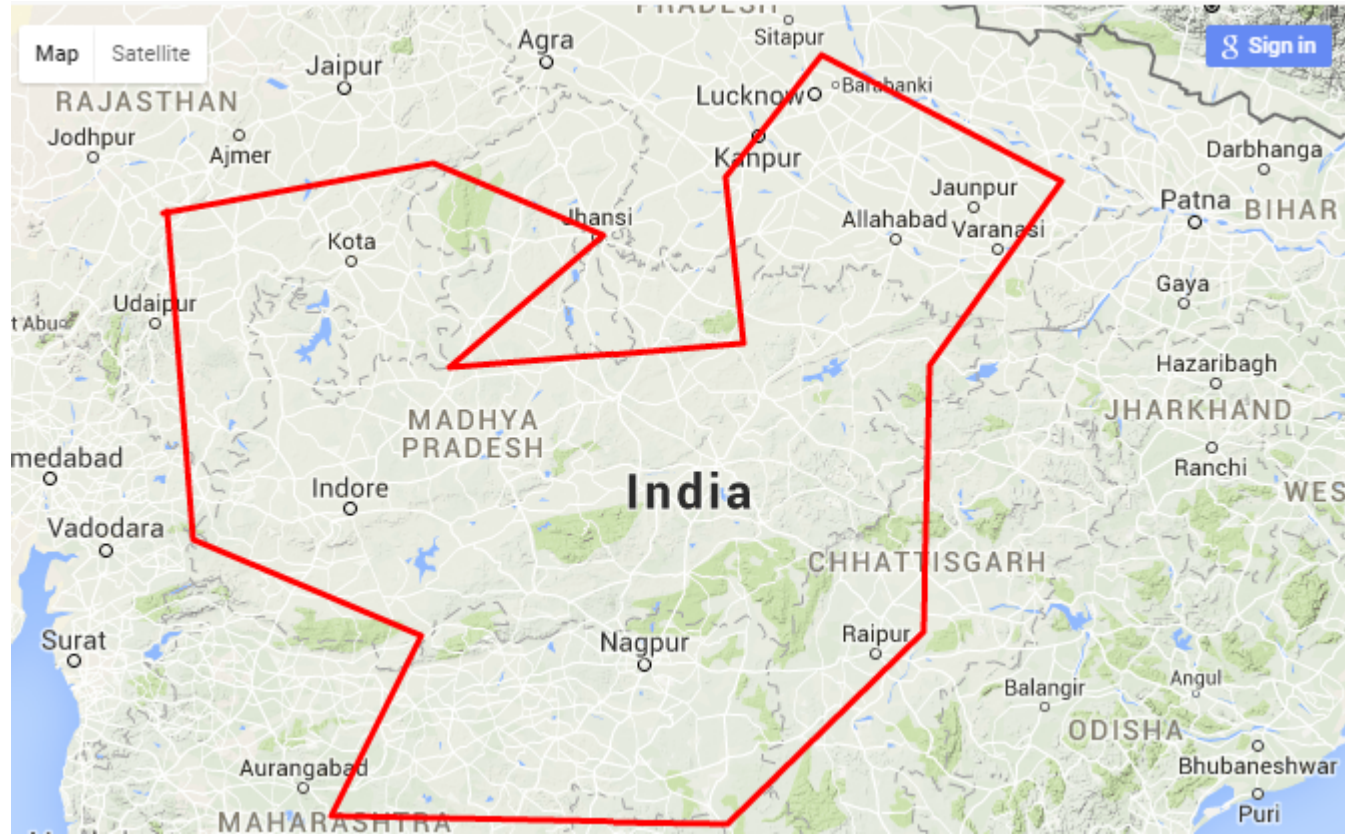
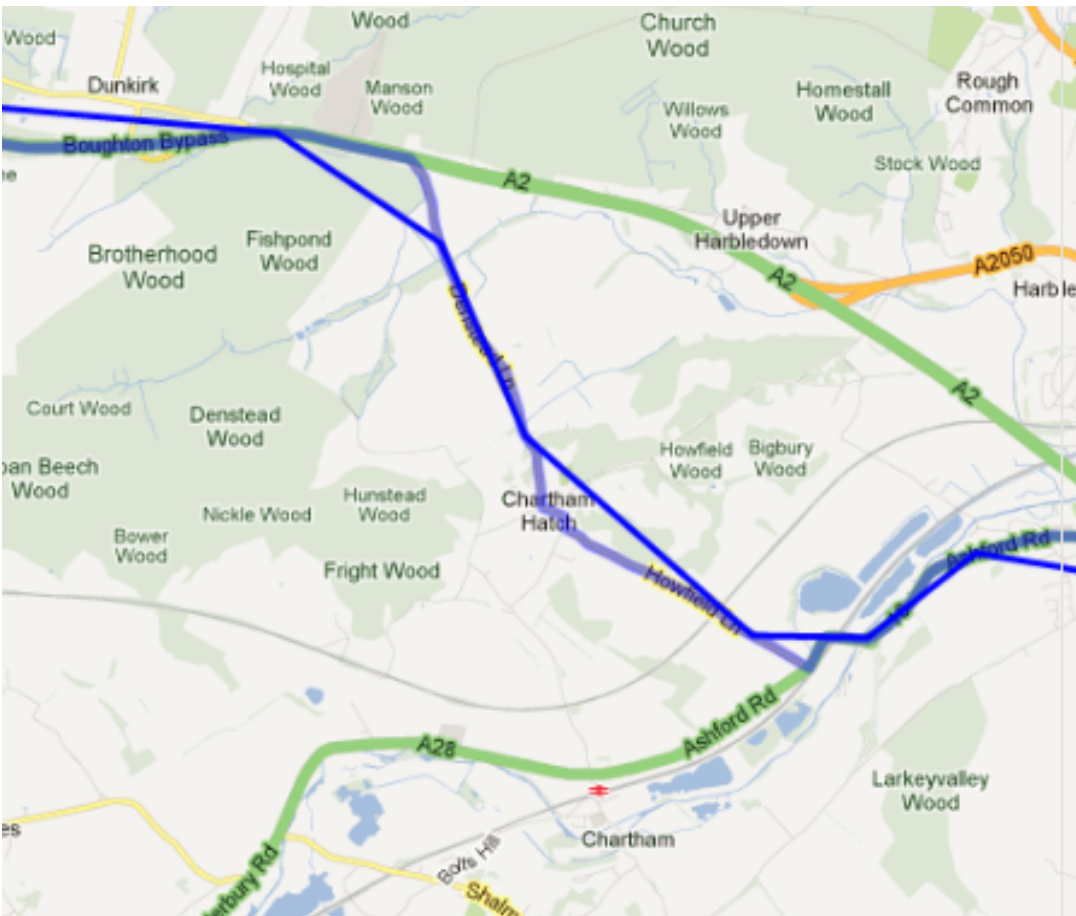
Google Map API



Google Maps



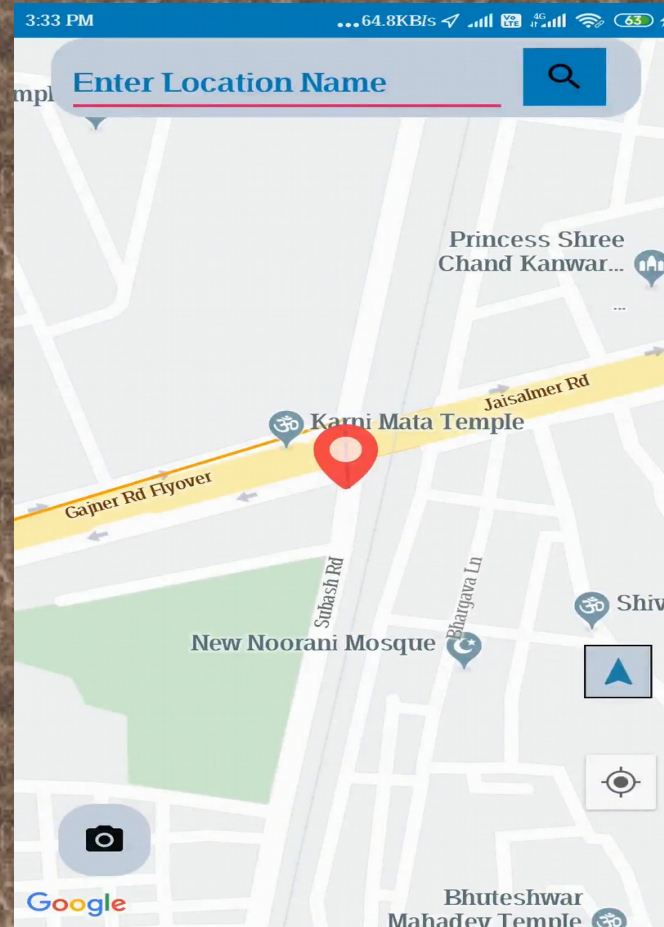
Polyline



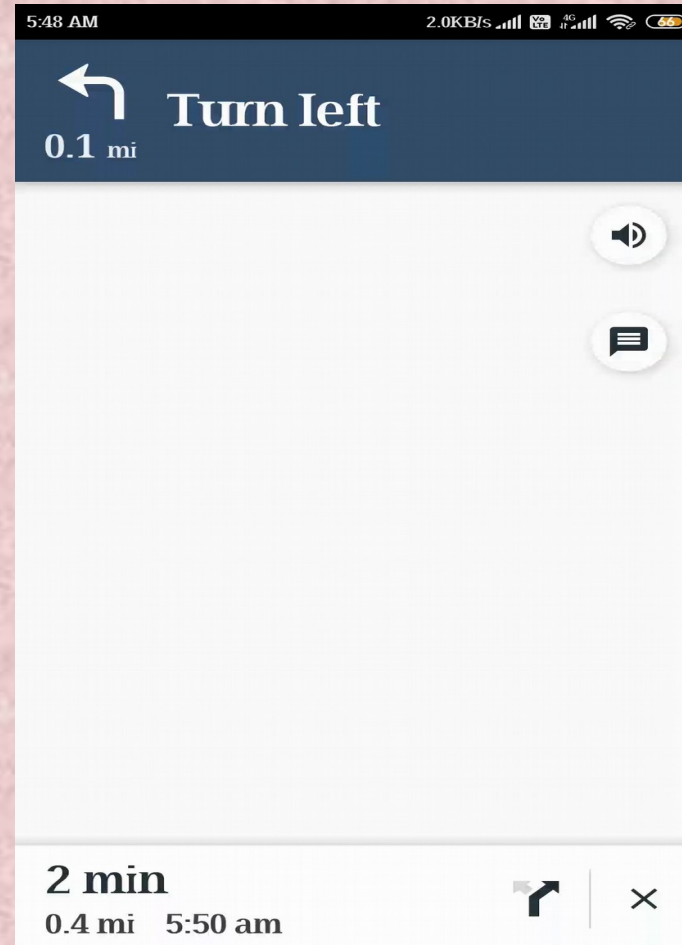
App's
icon



Demo Video of the App



Demo Video Of Navigation



Any Questions



Thank you!

