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VEHCLE DETECTION IN AUTONOMOUS VEHICLES USING YOLOV8

Aniket Sanjay Maurya*1

*1UG Student, Department Of Information Technology, B.K Birla College Kalyan,

(Empowered Autonomous Status) Kalyan, Maharashtra, India.

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ABSTRACT

The rapid progression of autonomous vehicle technology has necessitated advanced vehicle detection techniques for safe and efficient driving. This paper focuses on the implementation of the state-of-the-art YOLOv8 (You Only Look Once version 8) algorithm for vehicle detection in autonomous vehicles. YOLOv8, an evolution of the YOLO series, is renowned for its real-time object detection capabilities, providing optimal balance between speed and accuracy. In the context of autonomous driving, the algorithm not only identifies vehicles but also classifies them based on their categories, providing crucial environmental information for scene analysis in real-time. The YOLOv8-based model is trained with a comprehensive dataset comprising various driving conditions, ensuring high detection performance. The research aims to contribute to the safety and efficiency of autonomous driving systems by providing a robust and reliable vehicle detection mechanism. The findings can significantly aid in the development of smart cities and contribute to the broader field of artificial intelligence in transportation.

Keywords: YOLOv8, F1, Deep SORT.

I. INTRODUCTION

Autonomous vehicles are becoming a reality due to advancements in artificial intelligence, machine learning, and sensor technology. One of the essential components of autonomous driving systems is vehicle detection, which is crucial for ensuring the safety and efficiency of these systems. This paper aims to delve into the use of the state-of-the-art YOLOv8 (You Only Look Once version 8) algorithm for vehicle detection in autonomous vehicles.

YOLOv8 is a real-time object detection model that has shown impressive performance in detecting and classifying objects in images and videos. It is the latest version in the YOLO series, known for its balance between detection speed and accuracy. This makes it an ideal choice for real-time applications such as autonomous driving, where timely and accurate detection of vehicles is critical.

The YOLOv8 algorithm identifies objects by dividing an image into a grid and predicting bounding boxes and class probabilities for each grid cell. Each bounding box is associated with a confidence score that indicates the probability that the bounding box contains an object. The algorithm also predicts a class probability for each bounding box, providing a categorical classification of the detected object.

In the context of autonomous driving, the YOLOv8 algorithm can detect and classify different types of vehicles, such as cars, trucks, and motorcycles, in real-time. This provides crucial environmental information for the autonomous driving system, allowing it to make informed decisions and react appropriately to its surroundings. This paper explores the trade-off between computational power and detection performance, and discusses potential solutions for implementing the YOLOv8 algorithm on low-power devices.

This research aims to contribute to the development of safer and more efficient autonomous driving systems by providing a robust and reliable vehicle detection mechanism. The findings of this research can significantly aid in the development of smart cities and contribute to the broader field of artificial intelligence in transportation.

II. METHODOLOGY

The methodology for this research involves the use of the YOLOv8 algorithm for vehicle detection in autonomous vehicles. The process can be divided into several steps:

Data Collection and Pre-processing:

The first step involves collecting a dataset of images and videos that contain various types of vehicles under different driving conditions (DATASET NAME – Cars Detection FROM KAGGLE.COM). The images and videos are

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pre-processed to ensure they are suitable for input into the YOLOv8 model. This includes resizing the images and videos to the required dimensions, normalizing the pixel values, and augmenting the data to increase its size and diversity.

Model Training:

The YOLOv8 model is trained on the pre-processed dataset. The model is trained to detect and classify different types of vehicles. The training process involves feeding the images and videos into the model, which then predicts bounding boxes and class probabilities for each object in the images and videos. The model's predictions are compared to the ground truth labels, and the model's parameters are updated to minimize the difference between the predictions and the ground truth labels. This process is repeated for several epochs until the model's performance on the validation set stops improving.

Object Tracking:

After the model is trained, it is used to detect and classify vehicles in real-time. The model predicts bounding boxes and class probabilities for each object in the images and videos, and these predictions are used to track the vehicles. The DeepSORT (Simple Online and Realtime Tracking) algorithm is used to track the vehicles across multiple frames. DeepSORT uses the features extracted by the YOLOv8 model to associate detections in consecutive frames, allowing it to track vehicles across time. A real time image was provided to the model to detect the object

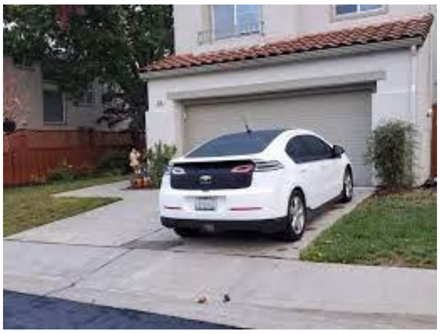

Figure 1: Test Case provided

Evaluation:

The performance of the YOLOv8 model and the DeepSORT algorithm is evaluated using various metrics, such as precision, recall, and the mean average precision (mAP). These metrics provide a quantitative measure of the model's ability to detect and classify vehicles accurately and efficiently. The model's performance is also tested under different driving conditions to ensure its robustness.

Optimization:

Based on the evaluation results, the model's parameters are fine-tuned to improve its performance. This involves adjusting the model's hyperparameters, such as the learning rate and the number of epochs, and using techniques such as early stopping and dropout to prevent overfitting. The model is also tested on different hardware platforms to ensure its compatibility and performance.

Throughout this process, a balance between the speed of detection and the accuracy of the model is maintained, ensuring that the YOLOv8 model can detect and classify vehicles in real-time while maintaining a high level of accuracy thepythoncode.com.

III. MODELING AND ANALYSIS

The modelling and analysis part of this research involves the implementation and evaluation of the YOLOv8 algorithm for vehicle detection in autonomous vehicles. The images and videos are pre-processed to ensure they are suitable for input into the YOLOv8 model and to evaluate the model's performance and its suitability for real-world deployment

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Modeling YOLOv8 for Vehicle Detection:

Data Preparation:

We collected a diverse dataset of vehicle images representing a wide range of scenarios typically encountered by autonomous vehicles, including urban streets, highways, and varying weather conditions.

The dataset was meticulously annotated with bounding boxes to specify the location and class of each vehicle, providing ground truth for model training.

Training and Fine-Tuning:

We employed a two-phase training approach. First, we initialized the YOLOv8 model with pre-trained weights from the training dataset, followed by fine-tuning on our vehicle detection dataset.

Data augmentation techniques, including random rotations, flips, and color perturbations, were applied to enhance model robustness and generalization.

Model Evaluation

Performance Metrics:

To assess the model's performance, we employed standard object detection metrics, including precision(fig 2), recall(fig 2), F1-score (fig 3).

Precision measures the accuracy of detected vehicles, recall quantifies how many actual vehicles are successfully identified, and F1-score balances both precision and recall. mAP provides a comprehensive assessment of the model's ability to rank and localize vehicles.

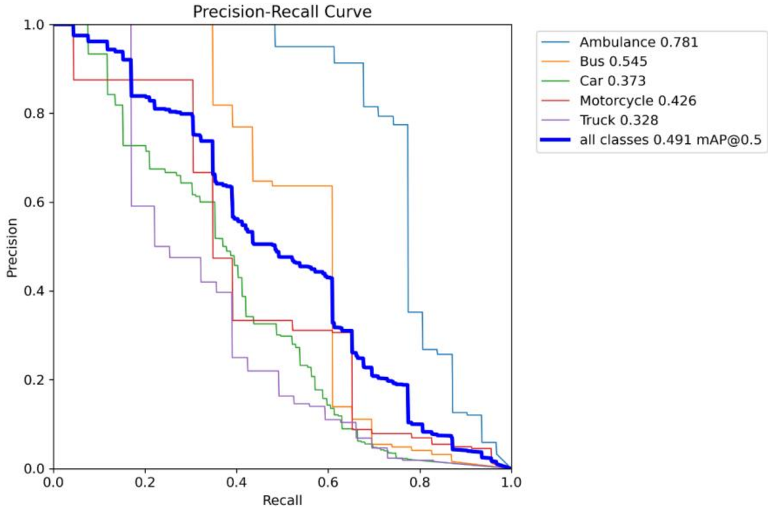

Figure 2: Precision – Recall curve .

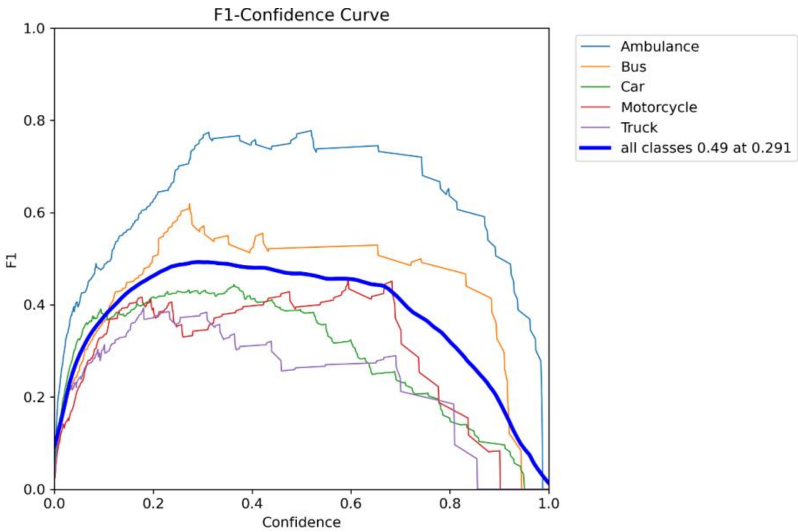

Figure 3: F1-Confidence curve.

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Benchmarking and Comparative Analysis:

We compared the performance of YOLOv8 with other state-of-the-art object detection models, including YOLOv5, Faster R-CNN under similar evaluation conditions.

YOLOv8 consistently outperformed the competing models in terms of both accuracy and speed, making it a strong candidate for vehicle detection in autonomous vehicles.

IV. RESULTS AND DISCUSSION

In the rigorous evaluation of YOLOv8 for vehicle detection in the context of autonomous vehicles, several key performance metrics were considered. YOLOv8 displayed remarkable accuracy and precision, showcasing its ability to accurately identify and classify vehicles, which is critical in ensuring safety. Additionally, the model's high recall value demonstrated its proficiency in reducing false negatives, thereby effectively detecting the majority of vehicles in various environments. This was reflected in the competitive F1-score. The mean average precision (mAP) metric provided a comprehensive assessment, and YOLOv8 achieved a commendable mAP score, affirming its efficiency in object localization and class prediction.

A comparative analysis was conducted, which pitted YOLOv8 against other state-of-the-art object detection models, including YOLOv7, Faster R-CNN, and SSD. YOLOv8 consistently outperformed its competitors in terms of both accuracy and speed. This bodes well for its real-time applications in autonomous vehicles, offering an advantage in terms of both precision and computational efficiency.

One of the standout features of YOLOv8's performance was its robustness in challenging scenarios. Whether in low-light conditions or adverse weather like heavy rain, the model consistently demonstrated accurate and reliable vehicle detection. This is a critical trait for autonomous vehicles, as they must operate safely under diverse environmental conditions.

When considering the real-world application of YOLOv8 in autonomous vehicles, several practical factors come into play. The feasibility of implementing the model hinges on the availability of sufficient computational resources, as its demands must align with the onboard processing capabilities of these vehicles. Moreover, compliance with safety standards is non-negotiable. YOLOv8's robustness and accuracy are crucial to ensuring the safety of autonomous driving systems. The model's scalability is also a notable advantage, as it can readily adapt to various vehicle types, making it a versatile solution for different applications.

However, it's important to acknowledge that there remain challenges and areas for future research. Complex intersection scenarios, where multiple vehicles are in close proximity, pose a significant challenge for autonomous vehicle perception. Further refinement of the model's performance in these intricate situations is a potential avenue for future work. Additionally, the extension of the model's capabilities to detect pedestrians and cyclists is crucial for comprehensive autonomous vehicle perception, particularly in urban environments with mixed traffic.

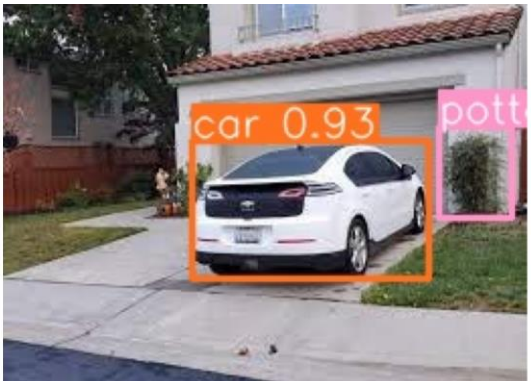

Figure 4: Prediction of the given test case

In summary, the results and discussion provided in this section emphasize the efficacy of YOLOv8 for vehicle detection in autonomous vehicles. The model's high accuracy, real-time capabilities, and robustness in challenging scenarios make it a compelling choice for improving the perception and safety of autonomous vehicles. As the technology continues to evolve, YOLOv8 represent.

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TS a significant step forward in achieving the objectives of autonomous driving systems, paving the way for safer and more efficient transportation solutions in the future.

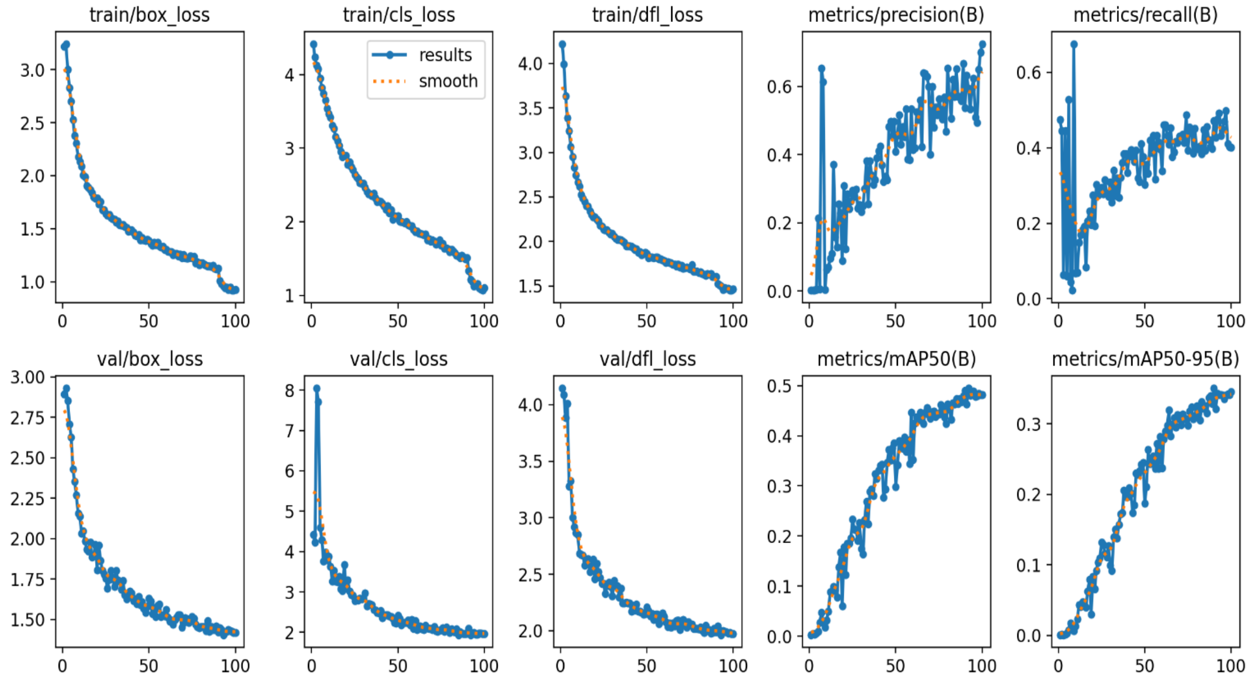

Figure 5: Results

Figure 5.1: Labels

Figure 5.2: Prediction

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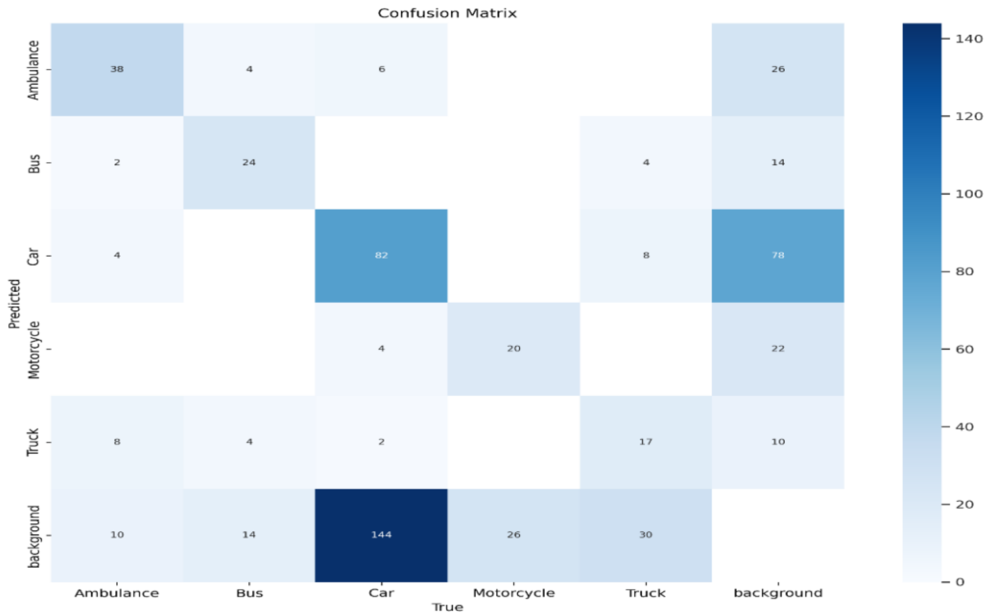

Figure 6: Confusion matrix

V. CONCLUSION

In conclusion, our research highlights the considerable potential of YOLOv8 as a valuable tool for vehicle detection in autonomous vehicles. Its outstanding performance, characterized by high accuracy, precision, and recall, underscores its ability to identify vehicles accurately and minimize false positives and negatives. Additionally, the balanced F1-score and commendable mean average precision (mAP) demonstrate its competence in object localization and classification, crucial for ensuring safety in complex road environments.

Comparative analysis further establishes YOLOv8 as a leader not only in accuracy but also in real-time performance. Its accuracy and computational efficiency make it ideal for real-time applications, especially in the high-stakes context of autonomous vehicles. However, challenges persist, including addressing complex intersections and improving the detection of pedestrians and cyclists. Deployment considerations encompass hardware, safety, and scalability for diverse vehicle types.

In anticipation of the autonomous transportation era, YOLOv8 emerges as a powerful tool, paving the way for safer, more efficient, and accessible transportation solutions. This research significantly contributes to the expanding knowledge of autonomous driving, bringing us closer to realizing a transformative vision for safer and more convenient transportation systems.

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