Spatial Ray Features for Real-Time Ego-Lane Extraction

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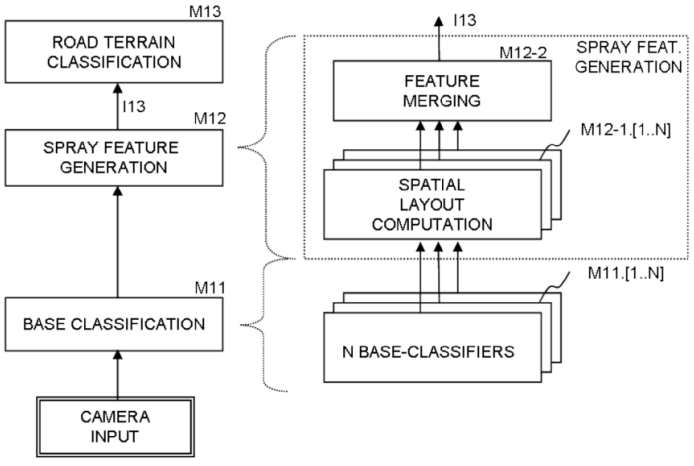

- Road classification in in unconstrained environments
- Extending local appearance-based road classification with a spatial feature generation and classification
- Local properties from base classifiers on patches from monocular camera images
- Output of classifiers represented in a metric confidence map
- Spatial ray features (SPRAY) from these confidence maps
- Final road-terrain classification based on local visual properties and their spatial layout
- No an explicit lane model
- In real-time with approximately 25 Hz on a GPU