Automatic Vacant Parking Places Management System Using Multicamera Vehicle Detection

Madhavi Karanam[1*], *Akhil Kumar* Reddy[2], *Pranit* Mathyam[3], *Azeemuddin* Mohammed[4] , and *Sandeep* Naik[5].

[1]Department of CSE, Gokaraju Rangaraju Institute of Engineering and Technology, India
[2]Department of CSE, Gokaraju Rangaraju Institute of Engineering and Technology, India
[3]Department of CSE, Gokaraju Rangaraju Institute of Engineering and Technology, India
[4]Department of CSE, Gokaraju Rangaraju Institute of Engineering and Technology, India
[5]Department of CSE, Gokaraju Rangaraju Institute of Engineering and Technology, India

Abstract. A multicamera system for detecting cars and mapping them into parking spaces in a parking lot is described in this study. A limited number of sequences and without more difficult reality conditions (illumination changes and various weather conditions) were used to evaluate approaches from a cutting-edge system that function correctly under controlled conditions. However, the majority of them only provide parts of systems, typically detectors, rather than the entire system. The proposed system was made to work in real-world situations that take into account a variety of occlusion scenarios, changes in lighting, and weather. For the purpose of design and validation, a brand-new multicamera data set was recorded. Two of the system's object detector results are shown, and several provided postprocessing stages are used to build the system. The findings clearly indicate that the suggested method works appropriately in demanding settings such as near entire occlusions, lighting variations, and varying weather conditions.

1 Introduction

Parking lots are a popular service that gets a lot of money every year. These parking lots need a lot of money and effort to keep clean, especially if there are a lot of them, like at airports or big business districts. Computer vision has many advantages over using invasive sensors like induction loops or other weight-in-motion sensors to solve this problem [1]. Additionally, a vision-based system may provide video surveillance and navigation of parking spots. By moving cars to areas with lower occupancy and directing them in a faster direction, these systems make it possible to decongest congested parking lots. The majority of parking lots have surveillance cameras, so in many cases, the only option is to analyze the

* Corresponding Author: bmadhaviranjan@yahoo.com

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data from the cameras that are already in place or to complete the deployment by adding additional cameras to provide the system with full coverage [2].

2 Related work

An algorithm for detecting parking lot occupancy is shown in this work, which uses an unsupervised vision-based method to identify occupants in parking garages. The suggested method merely processes a few edges every instant and has a modest computing complexity. Three important handling steps make up the strategy. In the first stage, the unfinished image that the camera framework captured is preprocessed. The shadows in the image have been greatly reduced or eliminated. The image warping is then corrected. The ideal correspondences between at least one fixed camera and apparent parking spaces are set forth in the next stage. This approach takes obstacles into account at every step. Finally, the parking situation is not unchangeable. The information gathered about parking lot occupants could be.

A framework for hierarchical Bayesian generation for the discovery of unoccupied parking spaces. From the perspective of scene understanding, a three-layer Bayesian hierarchical framework (BHF) for strong vacant parking space ID is developed in this paper. The difficulties in choosing a vacant leaving location are actually caused by emotional splendour variations, shadow influence, vision distortion, and vehicle between hindrance. Incorporating a hidden marking layer between a perception layer and a scene layer, the BHF provides a purposeful generative structure to recreate these variations. The proposed BHF treats the problem of brightness variations as a variety characterisation issue, and it tends to it through a grouping cycle from the perception layer to the naming layer, through the obstacle design, viewpoint bending, and shadow impact. The relationships between the scene layer and the marking layer strongly illustrate this. A combined Bayesian improvement problem with shadow production, impediment age, and item grouping models is how the BHF framework approaches the identification of vacant parking spaces and the marking of scene state[2]. Utilising outside parking area accounts collected from dawn to dusk, the accuracy of the framework was assessed. The experiment findings showed how the suggested structure can precisely locate shaded areas, quickly label areas for cars and the ground, calculate the number of abandoned spaces, and deal with brightness changes.

Using picture segmentation, a technique for parking car detection. A method of individual vehicle recognition using grayscale photos obtained from a high region is provided for directing arriving cars to discharge cells in a parking garage and other like applications. Each picture location related to a cell is divided up according to thickness (dim level) in the suggested method, and the distribution of section region is examined to determine whether a vehicle is accessible. The methodology may only be applied to parking lots that are regularly used because reference photos taken in an empty situation are not required. Since shape attributes are not used, auto shape is not given much consideration when recognising objects. The suggested method was tested for four days, from dawn to dusk, in a parking lot that was truly outside and in various climates[7]. The discoveries confirmed the effectiveness of the suggested technique, with a recognition rate of over 98.7%.

An automatic surveillance method for unattended parking lots in the open: An outdoor parking lot monitoring approach using video was suggested in this article. Parking lots were located in open, huge areas, making moving objects in taken images too small to collect the information and recognisable image for the item, identification, object behaviour analysis, or unlawful event alerting. A dual-camera device was built and calibrated by hand[5]. Several high-quality target photos can be taken from wide-open spaces using the calibrated settings. When there are numerous items in the monitoring region, the tracking method for one target may be swiftly switched to another. They are all kept in video-based DVR systems databases. The object images are also prepared for later retrieval.

Estimating the number of left-over vehicles, monitoring changes in left-over vehicles over time, and finding accessible vacancies are all goals of parking lot management. A clever solution for reducing manufacturing costs is an integrated vision-based framework. In this review, we offer a dream-based stopping-the-board framework for managing an outdoor parking area that makes use of four cameras positioned on the lofts of surrounding buildings and sends data, including continuous display, to an ITS middle data set through the internet. With the help of a remote, specialised device, this innovation enables drivers to quickly identify open parking spaces or monitor the parking lot where they parked their vehicles. All information photographs are first variety-overseen to ensure variety consistency, which helps to further develop precision[1]. A flexible parking garage setting model is then created. The correct shade of each parking place is determined in variety picture successions taken by a camera using a factual methodology, and a closer view is differentiated in light of variety data. Shadow ID will also influence the outcome in light of the splendour examination. With just a few cameras, a vision-based parking management system can cover a large area[4]. This innovation can quickly adapt to most situations by shifting the camera's location. Additionally, this framework is dependable and simple to introduce due to its basic hardware.

3 Proposed approach

Most of parking lots have surveillance cameras promptly accessible, so generally speaking, the arrangement comprises basically of properly handling the data got from the all-around introduced cameras or finishing the sending by adding extra cameras to give full inclusion that permits the framework to work. Since object location calculations have advanced as of late, utilizing their discoveries for the right working of independent stopping the executive's systems is currently possible. The earlier strategies were generally founded on picture division or machine learning (SVMs, NN) over spot patches [4].

Advantages

1. The findings clearly indicate that the suggested method works appropriately in demanding settings such as near entire occlusions, lighting variations, and varying weather conditions.
2. The suggested system has a significant advantage over picture segmentation-based methods in terms of resilience against changeable backdrop.
3. The ability to endure "object occlusions" is another benefit of detection-based systems. Despite the fact that some of the current systems

limitations

1. Approaches from a cutting-edge system that perform correctly in controlled circumstances have been evaluated using a modest number of sequences and without more difficult reality conditions (illumination changes and different weather conditions).

2. On the other hand, the majority of them do not give whole systems, but rather merely pieces of them, often detectors.

The International Pittsburgh Airport parking lot was chosen as the target scenario for the proposed framework relying on the prerequisite that current stopping surveillance cameras be used, staying away from the arrangement of extra cameras or other sensor gear. The recommended framework has been made for sensible circumstances that consider different kinds of impediment, lighting vacillations, and ecological factors. For plan and approval purposes, a new multicamera informational collection has been recorded. The framework is based on various potential postprocessing steps and existing item finders (the consequences of two of them are shown).

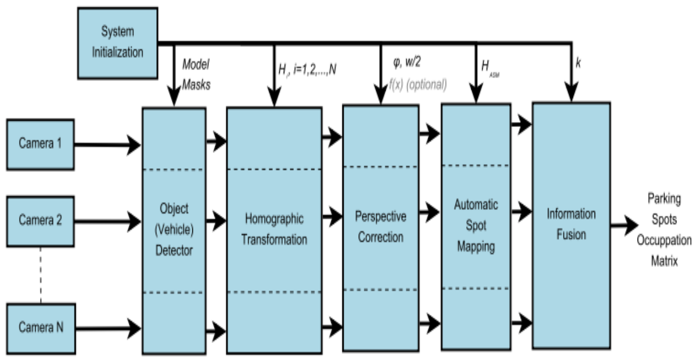

Fig.1: Block diagram for System architecture

4 Implementation

To carry out the aforementioned project, we created the following modules that

- import the packages: This will import the required packages from our software.
- Defining the Mask class function
- RCNN - Configuration for the Mask-RCNN library Function for Boxes - Filter a list of Mask R-CNN detection results to return just the identified vehicles / trucks
- Loading the Model: This model will be loaded.
- Loading the Video for Analysis: This video will be loaded. The video will be loaded
- Prediction: Using this module the final result is shown in the frontend using the Flask Framework

The following algorithm was utilized in this project:

Mask R-CNN is a state-of-the-art model for division that was based on top of Faster R-CNN. Quicker R-CNN is a district based convolutional brain network that produces jumping boxes and class marks for everything, alongside a certainty score. The photographs that have been pre-handled and commented on are used to prepare and confirm the Mask R-CNN Classifier. Our exploratory discoveries show that harm can be really related to 95.13% exactness on a custom-tailored dataset and 96.87% precision on haphazardly chosen photographs. Mask R-CNN predicts the cover utilizing a completely connected network. This ConvNet acknowledges a return for capital invested as information and returns the m*m veil portrayal as result. We furthermore upscale this cover for induction on the information picture and utilize 1*1 convolution to diminish the channels to 256.

Simulation and Result Analysis

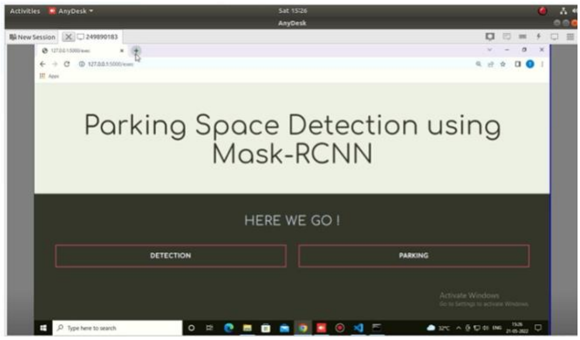

Fig.2: Home page of proposed system

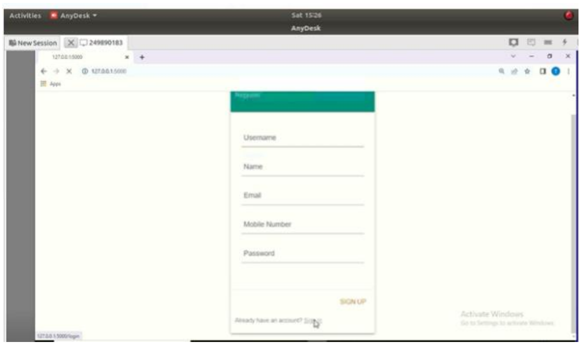

Fig.3: Registration of user

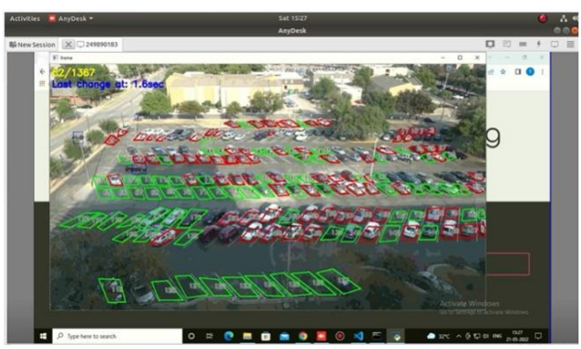

Fig.4: Detection of empty parking spaces

Object	Actual Length (mm)	Actual Breadth (mm)	Actual Area (mm*mm)	Observed Length (mm)	Observed Breadth (mm)	Observed Area (mm*mm)	Accuracy(%)
Mobile	155	72	11160	153.29	70.29	10774.47	96.54
Pen	120	13	1560	119.10	13.09	1559.19	99.95
Book	275	164	45100	276.01	163.5	45127.63	99.94
Box	302	305	92110	294.50	310.1	91324.45	99.14
Wallet	91	73	6643	92.74	74.69	6926.75	95.72
Pencil Box	140	45	6300	141.1	45.0	6349.5	99.21
Adapter	34	47	1598	34.99	48.46	1695.61	93.89

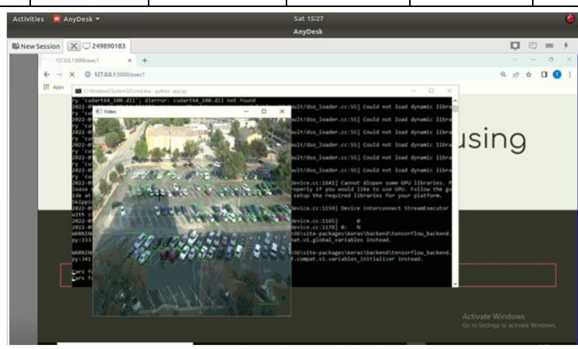

Fig 5: Final result

5 Conclusion

In order to manage vacant parking spaces in a parking lot, this paper proposes a multicamera system that detects vehicles and maps them into parking spaces. The system is designed in a way that, following a quick setup, existing parking lot security cameras may be used for the suggested system, negating the need for a brand-new camera deployment. The created system must handle conditions that are more complicated than those currently possible, such as nearly total occlusions and environmental variables (cloudy scenarios, rain, snow, etc.), which restrict or lessen their performance. It is not possible to execute an accurate background extraction in this scenario with such a variable backdrop, nor is it viable to label and describe the areas behind some parked automobiles because they completely obscure some of the sites behind them.

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