

ABSTRACT

The master's thesis consists of 133 pages and encloses 51 figures, 35 tables and 30 references.

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In the master's thesis a lane detection algorithm was developed. The prototype of unmanned with a camera for capturing road lines and the BeagleBone Black development board for the implementation of computer vision techniques has been developed.

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The algorithm of debugging the computer vision system was developed, which allows to quickly reconfigure the system for work on the new markup.

The developed prototype of a unmanned electric vehicle allows for the research of new algorithms for the detection of road marking lines and to investigate the quality of control methods of tracking devices.

AUTONOMOUS ELECTRIC VEHICLE, LANE DETECTION, PARABOLIC MODEL OF MOVEMENT, COMPUTER VISION, OPENCV, HOUGH LANE DETECTION, CANNY EDGE DETECTION, BEAGLEBONE BLACK

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