

## MOTIVATION



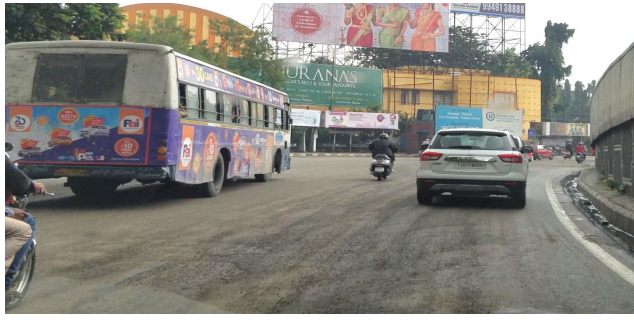
Pothole



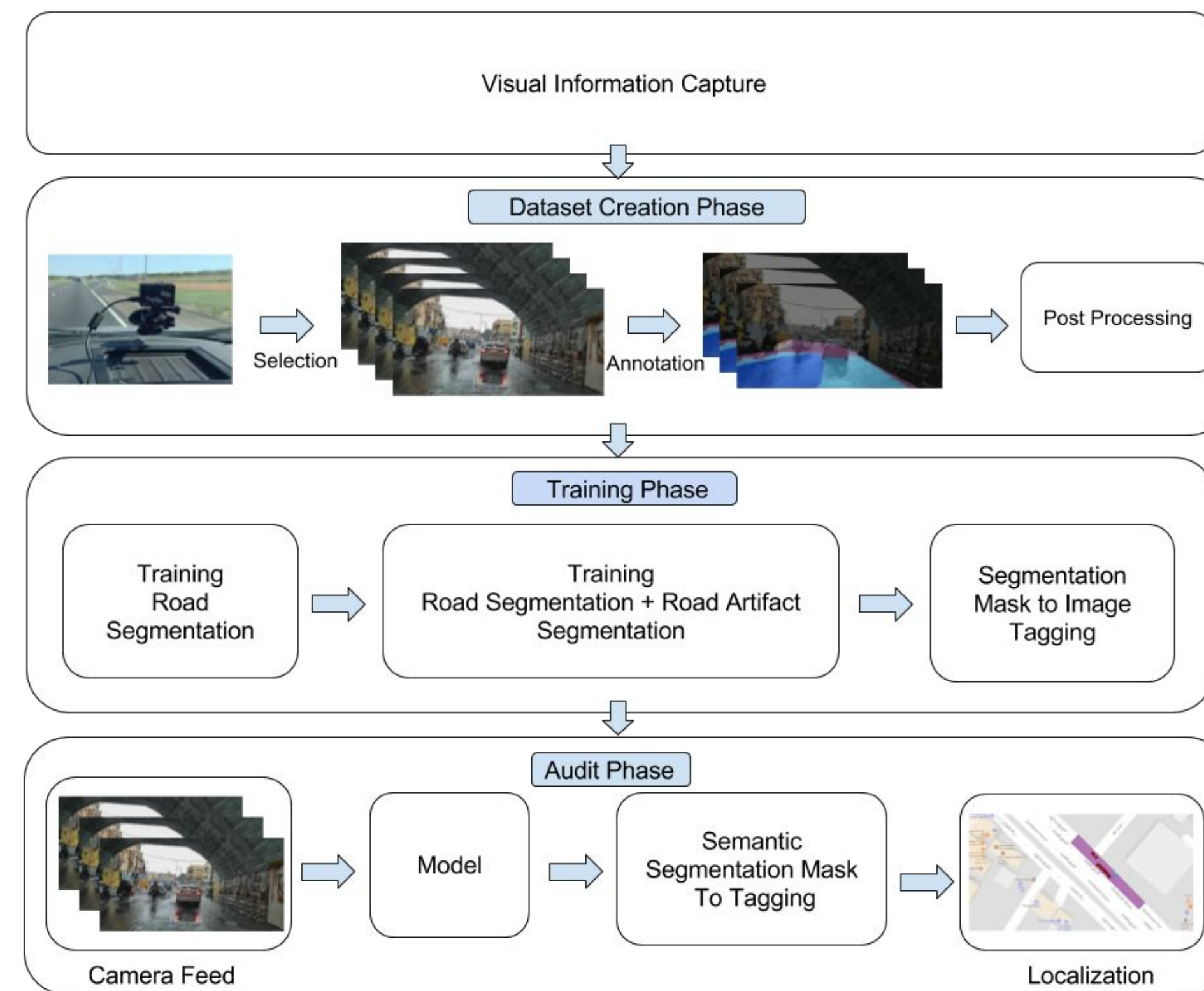
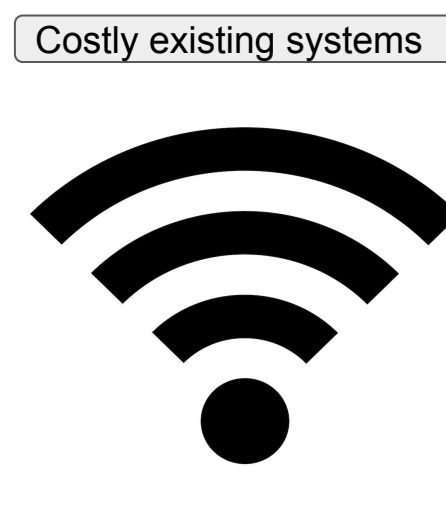
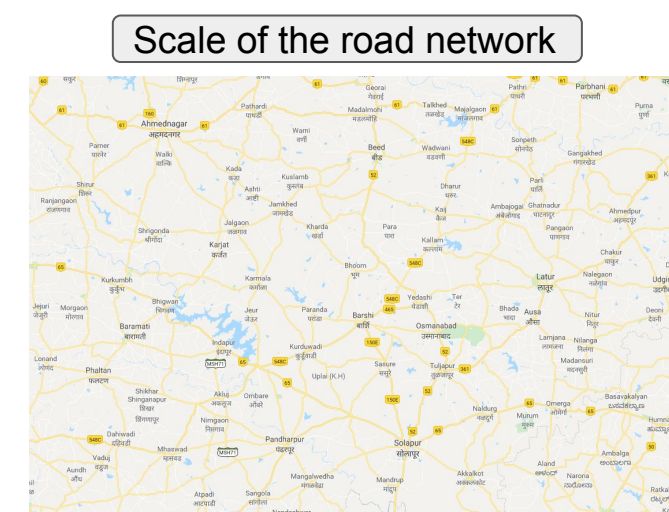
Water-log



Muddy-area



Rough Road



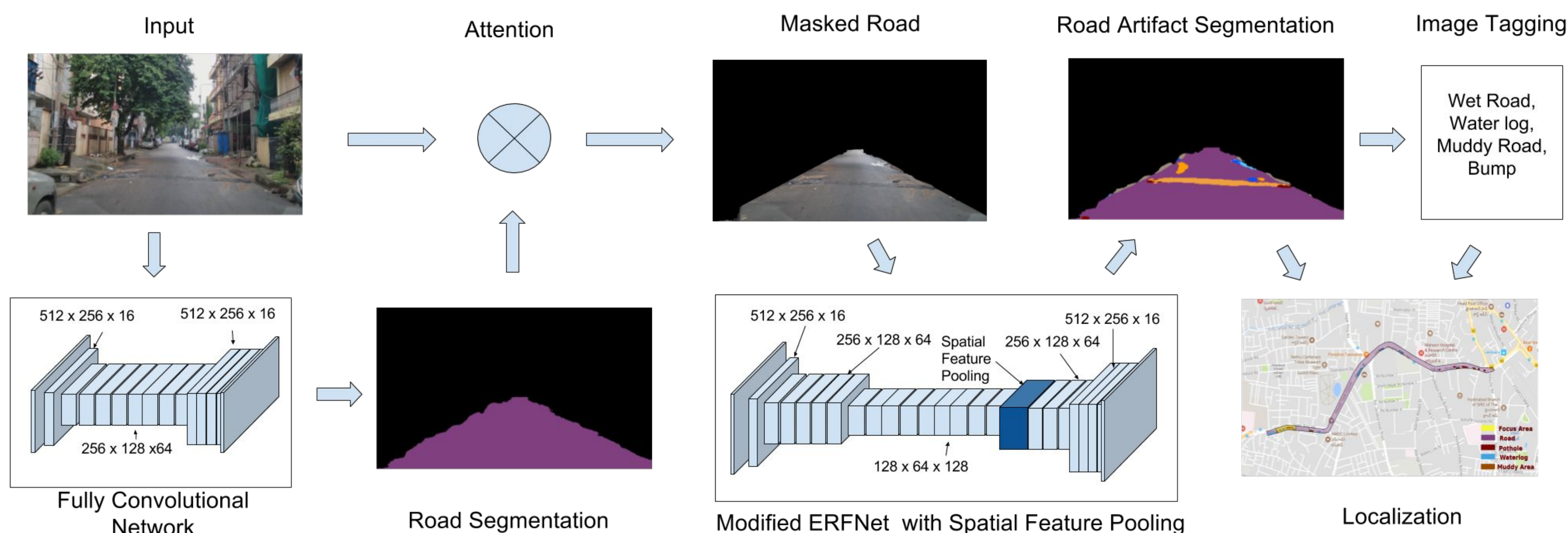
## QUALITATIVE RESULTS



■ Pothole ■ Water-log ■ Muddy-Area ■ Obstruction ■ Cement road  
■ Wet Road ■ Shoulder ■ Rough Road ■ Bumps

## METHOD

- We first segment the road, use it for an attention mechanism for obtaining the road pixels.
- Then use a powerful semantic segmentation model to segment multiple road defects.
- Finally, we tag the image frame for the defects and localize it in the map using GPS.



## RESULTS

Method (Category Level)	IoU (%)	wIoU (%)	fps (1024 × 512)
ERFNet (Fine-tuned)	41.8	59.8	41.7
ERFNet (Scratch)	42.1	59.8	41.7
Our refined ERFNet	45.7	60.7	26.2

Method (Class Level)	IoU (%)	wIoU (%)	fps (1024 × 512)
ERFNet (Fine-tuned)	24.1	55.2	41.7
ERFNet (Scratch)	24.4	57.2	41.7
Our refined ERFNet	28.1	59.0	26.2

Hierarchy(Our Method)	IoU(%)
Road-defects	65.1
Category level	45.7
Class Level(-cat4)	38.0
Class Level	28.1

Our Method (Image Tagging)	Precision (%)	Recall (%)
Pot hole	59.3	83.3
Rough Road	67.7	61.7
Cement Road	6.2	25.0
Obstruction	6.6	100.0
Wet Road	81.3	53.3
Water log	56.2	54.5
Muddy Road	74.1	76.6
Bumps	28.5	50.0
Shoulder	16.0	25.0

