

In [18]:

```
import scipy.misc
import random
import imageio
from skimage.transform import resize
xs = []
ys = []

#points to the end of the last batch
train_batch_pointer = 0
val_batch_pointer = 0

#read data.txt
with open("driving_dataset/data.txt") as f:
    for line in f:
        xs.append("driving_dataset/" + line.split()[0])
        #the paper by Nvidia uses the inverse of the turning radius,
        #but steering wheel angle is proportional to the inverse of turning radius
        #so the steering wheel angle in radians is used as the output
        ys.append(float(line.split()[1]) * scipy.pi / 180)

#get number of images
num_images = len(xs)

train_xs = xs[:int(len(xs) * 0.7)]
train_ys = ys[:int(len(xs) * 0.7)]

val_xs = xs[-int(len(xs) * 0.3):]
val_ys = ys[-int(len(xs) * 0.3):]

num_train_images = len(train_xs)
num_val_images = len(val_xs)

def LoadTrainBatch(batch_size):
    global train_batch_pointer
    x_out = []
    y_out = []
    for i in range(0, batch_size):
        image = full_image[-150:]/255.0
        image=resize(image,[66,200])
        x_out.append(resize(imread(train_xs[(train_batch_pointer + i) % num_train_images])[-150:]/2
55.0, [66, 200]))
        y_out.append([train_ys[(train_batch_pointer + i) % num_train_images]])
        train_batch_pointer += batch_size
    return x_out, y_out

def LoadValBatch(batch_size):
    global val_batch_pointer
    x_out = []
    y_out = []
    for i in range(0, batch_size):
        x_out.append(resize(imread(val_xs[(val_batch_pointer + i) % num_val_images])[-150:]/255.0,
[66, 200]))
        y_out.append([val_ys[(val_batch_pointer + i) % num_val_images]])
        val_batch_pointer += batch_size
    return x_out, y_out
```

In []:

```
import tensorflow as tf
import scipy

def weight_variable(shape):
    initial = tf.truncated_normal(shape, stddev=0.1)
    return tf.Variable(initial)

def bias_variable(shape):
    initial = tf.constant(0.1, shape=shape)
    return tf.Variable(initial)

def conv2d(x, W, stride):
```

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    return tf.nn.conv2d(x, W, strides=[1, stride, stride, 1], padding='VALID')

x = tf.placeholder(tf.float32, shape=[None, 66, 200, 3])
y_ = tf.placeholder(tf.float32, shape=[None, 1])

x_image = x

#first convolutional layer
W_conv1 = weight_variable([5, 5, 3, 24])
b_conv1 = bias_variable([24])

h_conv1 = tf.nn.relu(conv2d(x_image, W_conv1, 2) + b_conv1)

#second convolutional layer
W_conv2 = weight_variable([5, 5, 24, 36])
b_conv2 = bias_variable([36])

h_conv2 = tf.nn.relu(conv2d(h_conv1, W_conv2, 2) + b_conv2)

#third convolutional layer
W_conv3 = weight_variable([5, 5, 36, 48])
b_conv3 = bias_variable([48])

h_conv3 = tf.nn.relu(conv2d(h_conv2, W_conv3, 2) + b_conv3)

#fourth convolutional layer
W_conv4 = weight_variable([3, 3, 48, 64])
b_conv4 = bias_variable([64])

h_conv4 = tf.nn.relu(conv2d(h_conv3, W_conv4, 1) + b_conv4)

#fifth convolutional layer
W_conv5 = weight_variable([3, 3, 64, 64])
b_conv5 = bias_variable([64])

h_conv5 = tf.nn.relu(conv2d(h_conv4, W_conv5, 1) + b_conv5)

#FCL 1
W_fc1 = weight_variable([1152, 1164])
b_fc1 = bias_variable([1164])

h_conv5_flat = tf.reshape(h_conv5, [-1, 1152])
h_fc1 = tf.nn.relu(tf.matmul(h_conv5_flat, W_fc1) + b_fc1)

keep_prob = tf.placeholder(tf.float32)
h_fc1_drop = tf.nn.dropout(h_fc1, keep_prob)

#FCL 2
W_fc2 = weight_variable([1164, 100])
b_fc2 = bias_variable([100])

h_fc2 = tf.nn.relu(tf.matmul(h_fc1_drop, W_fc2) + b_fc2)

h_fc2_drop = tf.nn.dropout(h_fc2, keep_prob)

#FCL 3
W_fc3 = weight_variable([100, 50])
b_fc3 = bias_variable([50])

h_fc3 = tf.nn.relu(tf.matmul(h_fc2_drop, W_fc3) + b_fc3)

h_fc3_drop = tf.nn.dropout(h_fc3, keep_prob)

#FCL 3
W_fc4 = weight_variable([50, 10])
b_fc4 = bias_variable([10])

h_fc4 = tf.nn.relu(tf.matmul(h_fc3_drop, W_fc4) + b_fc4)

h_fc4_drop = tf.nn.dropout(h_fc4, keep_prob)

#Output
W_fc5 = weight_variable([10, 1])
b_fc5 = bias_variable([1])

y = tf.identity(tf.matmul(h_fc4_drop, W_fc5) + b_fc5) #scale the atan output

```

In []:

```
import os
import tensorflow as tf
from tensorflow.core.protobuf import saver_pb2
import driving_data
import model

LOGDIR = './save_identity_4_0.5'

sess = tf.InteractiveSession()

L2NormConst = 0.001

train_vars = tf.trainable_variables()

loss = tf.reduce_mean(tf.square(tf.subtract(model.y_, model.y))) + tf.add_n([tf.nn.l2_loss(v) for v
in train_vars]) * L2NormConst
train_step = tf.train.AdamOptimizer(1e-4).minimize(loss)
sess.run(tf.initialize_all_variables())

# create a summary to monitor cost tensor
tf.summary.scalar("loss", loss)
# merge all summaries into a single op
merged_summary_op = tf.summary.merge_all()

saver = tf.train.Saver(write_version = saver_pb2.SaverDef.V1)

# op to write logs to Tensorboard
logs_path = './save_identity_4_0.5'
summary_writer = tf.summary.FileWriter(logs_path, graph=tf.get_default_graph())

epochs = 30
batch_size = 100

# train over the dataset about 30 times
for epoch in range(epochs):
    for i in range(int(driving_data.num_images/batch_size)):
        xs, ys = driving_data.LoadTrainBatch(batch_size)
        train_step.run(feed_dict={model.x: xs, model.y_: ys, model.keep_prob: 0.5})
        if i % 10 == 0:
            xs, ys = driving_data.LoadValBatch(batch_size)
            loss_value = loss.eval(feed_dict={model.x:xs, model.y_: ys, model.keep_prob: 1.0})
            print("Epoch: %d, Step: %d, Loss: %g" % (epoch, epoch * batch_size + i, loss_value))

    # write logs at every iteration
    summary = merged_summary_op.eval(feed_dict={model.x:xs, model.y_: ys, model.keep_prob: 1.0})
    summary_writer.add_summary(summary, epoch * driving_data.num_images/batch_size + i)

    if i % batch_size == 0:
        if not os.path.exists(LOGDIR):
            os.makedirs(LOGDIR)
        checkpoint_path = os.path.join(LOGDIR, "model.ckpt")
        filename = saver.save(sess, checkpoint_path)
        print("Model saved in file: %s" % filename)

print("Run the command line:\n" \
      "--> tensorboard --logdir=./logs " \
      "\nThen open http://0.0.0.0:6006/ into your web browser")
```

In [1]:

```
#pip3 install opencv-python
import imageio
from skimage.transform import resize
import tensorflow as tf
import tensorflow.compat.v1 as tf
tf.disable_v2_behavior()
import scipy.misc
import model
import cv2
from subprocess import call
import math
from matplotlib.pyplot import imread
from PIL import Image
```

```

sess = tf.InteractiveSession()
saver = tf.train.Saver()
saver.restore(sess, "save_identity_4_0.5/model.ckpt")

img = cv2.imread('steering_wheel_image.jpg',0)
rows,cols = img.shape

smoothed_angle = 0

#read data.txt
xs = []
ys = []
with open("driving_dataset/data.txt") as f:
    for line in f:
        xs.append("driving_dataset/" + line.split()[0])
        #the paper by Nvidia uses the inverse of the turning radius,
        #but steering wheel angle is proportional to the inverse of turning radius
        #so the steering wheel angle in radians is used as the output
        ys.append(float(line.split()[1]) * scipy.pi / 180)

#get number of images
num_images = len(xs)

i = math.ceil(num_images*0.8)
print("Starting frameofvideo:" +str(i))

while(cv2.waitKey(10) != ord('q')):
    full_image =imread("driving_dataset/" + str(i) + ".jpg")
    image = full_image[-150:]/255.0
    image=resize(image,[66,200])
    degrees = model.y.eval(feed_dict={model.x: [image], model.keep_prob: 1.0})[0][0] * 180.0 /
scipy.pi
    #call("clear")
    #print("Predicted Steering angle: " + str(degrees))
    print("Steering angle: " + str(degrees) + " (pred)\t" + str(ys[i]*180/scipy.pi) + " (actual)")
    cv2.imshow("frame", cv2.cvtColor(full_image, cv2.COLOR_RGB2BGR))
    #make smooth angle transitions by turning the steering wheel based on the difference of the cu
rrent angle
    #and the predicted angle
    smoothed_angle += 0.2 * pow(abs((degrees - smoothed_angle)), 2.0 / 3.0) * (degrees -
smoothed_angle) / abs(degrees - smoothed_angle)
    M = cv2.getRotationMatrix2D((cols/2,rows/2),-smoothed_angle,1)
    dst = cv2.warpAffine(img,M,(cols,rows))
    cv2.imshow("steering wheel", dst)
    i += 1

cv2.destroyAllWindows()

```

WARNING:tensorflow:From C:\Users\nnagari\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\compat\v2_compat.py:65: disable_resource_variables (from tensorflow.python.ops.variable_scope) is deprecated and will be removed in a future version.

Instructions for updating:

non-resource variables are not supported in the long term

WARNING:tensorflow:From C:\Users\nnagari\Desktop\ML\Autopilot-TensorFlow-master\Autopilot-TensorFlow-master\model.py:63: calling dropout (from tensorflow.python.ops.nn_ops) with keep_prob is deprecated and will be removed in a future version.

Instructions for updating:

Please use `rate` instead of `keep_prob`. Rate should be set to `rate = 1 - keep_prob`.

INFO:tensorflow:Restoring parameters from save_identity_4_0.5/model.ckpt

Starting frameofvideo:36325

```

Steering angle: 5.401364395178035 (pred) -10.79 (actual)
Steering angle: 5.950197842632063 (pred) -10.08 (actual)
Steering angle: 6.092030989615609 (pred) -9.380000000000003 (actual)
Steering angle: 7.740087334447986 (pred) -7.559999999999999 (actual)
Steering angle: 7.924224111829652 (pred) -5.949999999999999 (actual)
Steering angle: 8.660908678913364 (pred) -3.23 (actual)
Steering angle: 6.5444217391022335 (pred) -0.81 (actual)
Steering angle: 5.497418626136394 (pred) 1.21 (actual)
Steering angle: 4.911337168930525 (pred) 3.4300000000000006 (actual)
Steering angle: 2.7522067968100665 (pred) 4.44 (actual)
Steering angle: 2.5421614043592498 (pred) 5.340000000000001 (actual)
Steering angle: 2.0271956633481416 (pred) 5.75 (actual)
Steering angle: 1.5291335733157574 (pred) 7.16 (actual)

```

Steering angle: 1.5204839925055826 (pred) 8.27 (actual)
Steering angle: 1.6479104562605735 (pred) 9.48 (actual)
Steering angle: 1.756668305466627 (pred) 0.0 (actual)
Steering angle: 1.695512605907331 (pred) 9.88 (actual)
Steering angle: 2.069781039049525 (pred) 9.979999999999999 (actual)
Steering angle: 1.9818598558453588 (pred) 10.389999999999999 (actual)
Steering angle: 1.745346199700273 (pred) 11.6 (actual)
Steering angle: 1.5288041234100103 (pred) 11.39 (actual)
Steering angle: 1.6036815662901558 (pred) 10.89 (actual)
Steering angle: 1.7373352415774943 (pred) 10.89 (actual)
Steering angle: 2.202024600438373 (pred) 10.89 (actual)
Steering angle: 3.7643089237776106 (pred) 10.59 (actual)
Steering angle: 2.702278754307508 (pred) 10.389999999999999 (actual)
Steering angle: 1.6877139172573516 (pred) 10.389999999999999 (actual)
Steering angle: 1.7954953695772107 (pred) 10.79 (actual)
Steering angle: 1.9414680380846077 (pred) 11.6 (actual)
Steering angle: 1.6814258743527086 (pred) 12.0 (actual)
Steering angle: 1.7078701256631765 (pred) 12.100000000000001 (actual)
Steering angle: 2.7672831587424005 (pred) 12.2 (actual)
Steering angle: 2.7600252289756155 (pred) 12.300000000000002 (actual)
Steering angle: 2.18664514886162 (pred) 12.61 (actual)
Steering angle: 1.9390347831927905 (pred) 13.01 (actual)
Steering angle: 1.8414877290139609 (pred) 13.71 (actual)
Steering angle: 1.7646799039196404 (pred) 14.420000000000002 (actual)
Steering angle: 1.6331964145193676 (pred) 15.13 (actual)
Steering angle: 1.5688832465728217 (pred) 16.24 (actual)
Steering angle: 1.5218005114681026 (pred) 17.75 (actual)
Steering angle: 1.580739921363435 (pred) 19.16 (actual)
Steering angle: 1.5415066744406472 (pred) 20.370000000000005 (actual)
Steering angle: 1.5205843109090171 (pred) 21.38 (actual)
Steering angle: 1.6322504333193208 (pred) 22.08 (actual)
Steering angle: 1.7494820926861272 (pred) 22.99 (actual)
Steering angle: 1.831882988937042 (pred) 23.9 (actual)
Steering angle: 1.6597886888357545 (pred) 24.810000000000002 (actual)
Steering angle: 1.8137887506086205 (pred) 25.71 (actual)
Steering angle: 1.766186494240157 (pred) 27.03 (actual)
Steering angle: 1.7469608991087464 (pred) 27.93 (actual)
Steering angle: 1.660371496071027 (pred) 28.939999999999998 (actual)
Steering angle: 1.5835440341828426 (pred) 29.75 (actual)
Steering angle: 1.5093867493733102 (pred) 30.76 (actual)
Steering angle: 1.6240518584377783 (pred) 31.66 (actual)
Steering angle: 1.6079805300424441 (pred) 32.67 (actual)
Steering angle: 1.7692177108494676 (pred) 34.18 (actual)
Steering angle: 2.0541774718906307 (pred) 35.5 (actual)
Steering angle: 1.8978828934434637 (pred) 36.400000000000006 (actual)
Steering angle: 1.704594302904215 (pred) 38.22 (actual)
Steering angle: 1.8857787310171432 (pred) 39.43 (actual)
Steering angle: 1.744381328758303 (pred) 41.04 (actual)
Steering angle: 1.6766992767253541 (pred) 42.86 (actual)
Steering angle: 1.750046330344594 (pred) 44.37 (actual)
Steering angle: 1.5508864451617788 (pred) 46.08 (actual)
Steering angle: 1.5806176182886096 (pred) 47.19 (actual)
Steering angle: 1.513481341059027 (pred) 47.39 (actual)
Steering angle: 1.477027127354788 (pred) 47.39 (actual)
Steering angle: 1.3626312771540063 (pred) 46.39 (actual)
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Steering angle: 1.3159979471523326 (pred) 47.09 (actual)
Steering angle: 1.3175197986767762 (pred) 49.21 (actual)
Steering angle: 1.3338258081031238 (pred) 50.62 (actual)
Steering angle: 1.4464892448539552 (pred) 50.720000000000006 (actual)
Steering angle: 1.5403844957043553 (pred) 51.63 (actual)
Steering angle: 3.2519089860169004 (pred) 52.34 (actual)
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Steering angle: 14.436781310906484 (pred) 52.54 (actual)
Steering angle: 8.984945659743463 (pred) 49.41 (actual)
Steering angle: 9.618931502466863 (pred) 47.599999999999994 (actual)
Steering angle: 9.260495981429287 (pred) 47.599999999999994 (actual)
Steering angle: 6.079884778837211 (pred) 47.599999999999994 (actual)
Steering angle: 4.383837817349032 (pred) 47.599999999999994 (actual)
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Steering angle: 8.373311611078929 (pred) 42.959999999999994 (actual)
Steering angle: 7.714886497731578 (pred) 43.86999999999999 (actual)
Steering angle: 8.218737599972371 (pred) 44.77 (actual)
Steering angle: 8.440017799834212 (pred) 45.57999999999999 (actual)
Steering angle: 8.926315315908074 (pred) 45.78 (actual)
Steering angle: 9.750589375134382 (pred) 45.98 (actual)
Steering angle: 9.726236335648702 (pred) 46.29 (actual)
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Steering angle: 9.113650329368598 (pred) 46.39 (actual)
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Steering angle: 7.834272228007877 (pred) 46.49 (actual)
Steering angle: 6.5460182958207245 (pred) 46.69 (actual)
Steering angle: 5.927064845686877 (pred) 46.989999999999995 (actual)
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Steering angle: 1.560349885700243 (pred) 47.39 (actual)
Steering angle: 2.2055613577679702 (pred) 47.7 (actual)
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Steering angle: 4.277429019608934 (pred) 47.7 (actual)
Steering angle: 5.517272278506328 (pred) 47.7 (actual)
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Steering angle: 8.981635579316945 (pred) 47.8 (actual)
Steering angle: 10.209242554316262 (pred) 48.0 (actual)
Steering angle: 10.074552931430903 (pred) 0.0 (actual)
Steering angle: 10.35281739953816 (pred) 48.5 (actual)
Steering angle: 13.311368480042544 (pred) 48.71000000000001 (actual)
Steering angle: 17.627562238285886 (pred) 48.91 (actual)
Steering angle: 24.767841996617214 (pred) 49.11 (actual)
Steering angle: 23.869798479260183 (pred) 49.21 (actual)
Steering angle: 22.320940386838487 (pred) 49.41 (actual)
Steering angle: 18.020062474035253 (pred) 49.92 (actual)
Steering angle: 20.56983697799813 (pred) 50.12 (actual)
Steering angle: 17.883059124568554 (pred) 50.22 (actual)
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Steering angle: 2.5945077607148157 (pred) 51.23 (actual)
Steering angle: 3.6760859315894945 (pred) 51.13 (actual)
Steering angle: 4.153172937567593 (pred) 51.030000000000001 (actual)
Steering angle: 5.017397200136129 (pred) 51.030000000000001 (actual)
Steering angle: 5.316468132002539 (pred) 51.030000000000001 (actual)
Steering angle: 6.644717944421994 (pred) 51.030000000000001 (actual)
Steering angle: 6.604807014667493 (pred) 51.030000000000001 (actual)
Steering angle: 6.537378106520658 (pred) 51.030000000000001 (actual)
Steering angle: 6.763823636942322 (pred) 51.030000000000001 (actual)
Steering angle: 5.993157598077328 (pred) 50.82 (actual)
Steering angle: 5.2675686733003015 (pred) 50.52 (actual)
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Steering angle: -0.7551482759575485 (pred) -6.55 (actual)
Steering angle: -0.5882649833061576 (pred) -6.659999999999999 (actual)
Steering angle: -0.8762850959823096 (pred) -6.860000000000001 (actual)
Steering angle: -1.1032384082800817 (pred) -7.06 (actual)
Steering angle: -0.9679692865323296 (pred) -7.36 (actual)
Steering angle: -0.7882731993282294 (pred) -7.559999999999999 (actual)
Steering angle: -0.6335457224087571 (pred) -7.659999999999998 (actual)
Steering angle: -0.34076902330592584 (pred) -7.659999999999998 (actual)
Steering angle: -0.2381221656946239 (pred) -7.659999999999998 (actual)
Steering angle: -0.45523168129452674 (pred) -7.659999999999998 (actual)
Steering angle: -0.6584306628760523 (pred) -7.659999999999998 (actual)
Steering angle: -0.7774765912411433 (pred) -7.659999999999998 (actual)
Steering angle: -0.6796740452986729 (pred) -7.659999999999998 (actual)
Steering angle: -0.38713768347726146 (pred) -7.659999999999998 (actual)
Steering angle: -0.4623372124654556 (pred) -7.760000000000002 (actual)
Steering angle: -0.23416257696672058 (pred) -7.87 (actual)
Steering angle: -0.19714935496759836 (pred) -7.969999999999999 (actual)
Steering angle: 0.04386817060487627 (pred) -8.17 (actual)
Steering angle: -0.022243364805792774 (pred) -8.27 (actual)
Steering angle: 0.06764598009639472 (pred) -8.37 (actual)
Steering angle: -0.15013054616464214 (pred) -8.37 (actual)
Steering angle: -0.30148497685118597 (pred) -8.469999999999999 (actual)
Steering angle: -0.32757544570698843 (pred) -8.570000000000002 (actual)
Steering angle: -0.5258801698613768 (pred) -8.67 (actual)
Steering angle: -0.5424011168031682 (pred) -8.77 (actual)
Steering angle: -0.4936858597651101 (pred) -8.77 (actual)
Steering angle: -0.3633805779966646 (pred) -8.87 (actual)
Steering angle: -0.4073315646452273 (pred) -8.97 (actual)
Steering angle: -0.46641867738136134 (pred) -8.97 (actual)
Steering angle: -0.4716087673769248 (pred) -8.97 (actual)
Steering angle: -0.5680437813815117 (pred) -8.97 (actual)
Steering angle: -0.6510006977195478 (pred) -9.08 (actual)
Steering angle: -0.6429190898275418 (pred) -9.28 (actual)
Steering angle: -0.6399031344221581 (pred) -9.380000000000003 (actual)
Steering angle: -0.8112004368246697 (pred) -9.58 (actual)
Steering angle: -1.105416171408258 (pred) -9.58 (actual)
Steering angle: -0.9097026502702433 (pred) -9.78 (actual)
Steering angle: -1.323578389913989 (pred) -9.88 (actual)
Steering angle: -1.526068739369126 (pred) -10.08 (actual)
Steering angle: -1.3124914987871774 (pred) -10.08 (actual)

```

KeyboardInterrupt

Traceback (most recent call last)

```

<ipython-input-1-eba1ed506385> in <module>
    45     image = full_image[-150:]/255.0
    46     image=resize(image,[66,200])
--> 47     degrees = model.y.eval(feed_dict={model.x: [image], model.keep_prob: 1.0})[0][0] * 180.0
/ scipy.pi
    48     #call("clear")
    49     #print("Predicted Steering angle: " + str(degrees))

```

```

~\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\framework\ops.py in eval(self, feed_dict, session)
    796
    797     """
--> 798     return _eval_using_default_session(self, feed_dict, self.graph, session)
    799
    800     def experimental_ref(self):

```

```

~\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\framework\ops.py in _eval_using_default_session(tensors, feed_dict, graph, session)
    5408         "the tensor's graph is different from the session's "
    5409         "graph.")
-> 5410     return session.run(tensors, feed_dict)
    5411
    5412

```

```

~\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\client\session.py in run(self, fetches, feed_dict, options, run_metadata)
    954     try:
    955         result = self._run(None, fetches, feed_dict, options_ptr,
--> 956                             run_metadata_ptr)
    957         if run_metadata:
    958             proto_data = tf_session.TF_GetBuffer(run_metadata_ptr)

```



```

990         proto_data = tf_session.TF_GetBuffer(run_metadata_ptr)

~\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\client\session.py in
_run(self, handle, fetches, feed_dict, options, run_metadata)
    1178     if final_fetches or final_targets or (handle and feed_dict_tensor):
    1179         results = self._do_run(handle, final_targets, final_fetches,
-> 1180                               feed_dict_tensor, options, run_metadata)
    1181     else:
    1182         results = []

~\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\client\session.py in
_do_run(self, handle, target_list, fetch_list, feed_dict, options, run_metadata)
    1357     if handle is None:
    1358         return self._do_call(_run_fn, feeds, fetches, targets, options,
-> 1359                             run_metadata)
    1360     else:
    1361         return self._do_call(_prun_fn, handle, feeds, fetches)

~\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\client\session.py in
_do_call(self, fn, *args)
    1363     def _do_call(self, fn, *args):
    1364         try:
-> 1365             return fn(*args)
    1366         except errors.OpError as e:
    1367             message = compat.as_text(e.message)

~\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\client\session.py in
_run_fn(feed_dict, fetch_list, target_list, options, run_metadata)
    1348     self._extend_graph()
    1349     return self._call_tf_sessionrun(options, feed_dict, fetch_list,
-> 1350                                     target_list, run_metadata)
    1351
    1352     def _prun_fn(handle, feed_dict, fetch_list):

~\AppData\Local\Continuum\anaconda3\lib\site-packages\tensorflow_core\python\client\session.py in
_call_tf_sessionrun(self, options, feed_dict, fetch_list, target_list, run_metadata)
    1441     return tf_session.TF_SessionRun_wrapper(self._session, options, feed_dict,
    1442                                             fetch_list, target_list,
-> 1443                                             run_metadata)
    1444
    1445     def _call_tf_sessionprun(self, handle, feed_dict, fetch_list):

```

KeyboardInterrupt:

In [9]:

```

import prettytable

table=prettytable.PrettyTable()

table.field_names=['Model activation','keepprob','Loss']

table.add_row(['identity','1e-4','0.4013'])
#table.add_row(['identity','1e-3','0.4425',""])

print(table)

```

```

+-----+-----+-----+
| Model activation | keepprob | Loss |
+-----+-----+-----+
| identity        | 1e-4    | 0.4013 |
+-----+-----+-----+

```

1. This model comparatively doing good when we compared below model but sometimes it will do mistakes but it is not best compare to base model.

In [11]:

```

import prettytable

table=prettytable.PrettyTable()

```

```

table.field_names=['Model activation','keepprob','Loss']

#table.add_row(['identity','1e-4','0.4013'])
table.add_row(['identity','1e-3','0.4425'])

print(table)

```

```

+-----+-----+-----+
| Model activation | keepprob | Loss |
+-----+-----+-----+
|      identity   |    1e-3  | 0.4425 |
+-----+-----+-----+

```

1. "Above model is not performing well compared to base model, in some situation model supposed to predict the -VE steering angle but it is predicting the +VE steering angle."