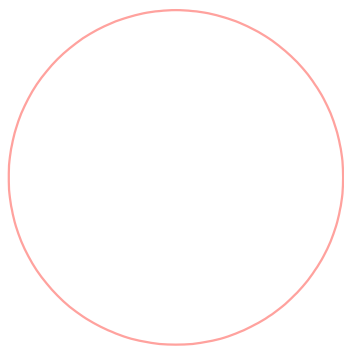


In [1]:

```
from pop import Pilot
cam=Pilot.Camera(width=380, height=300)
cam.show()
dataCollector=Pilot.Data_Collector(Pilot.Track_Follow, camera=cam)
```

In [2]:

```
dataCollector.show()
```



In [3]:

```
LF=Pilot.Track_Follow(camera=cam)
LF.load_datasets()
```

In [4]:

```
LF.train(times=5)
```

```
0 step loss : 0.021978715998253164
1 step loss : 0.016634451128761357
2 step loss : 0.015210113113556191
3 step loss : 0.014517479275992094
4 step loss : 0.01355965987627828
```

In [5]:

```
value=LF.run()
print(value)
```

```
{'x': -0.052792307, 'y': 0.015738895}
```

In [6]:

```
LF.show()
```

In [9]:

```
bot=Pilot.SerBot()

bot.setSpeed (40)
def drive(value):
    bot.forward()

    steer=value['x']

    if steer> 1:

        steer=1

    elif steer < -1:
        steer=-1

    bot.steering=steer*1.5
while True:
    LF.run(callback=drive)
```

```

-----
KeyboardInterrupt                                Traceback (most recent call last)
<ipython-input-9-3f7aae61c1a9> in <module>
    17     bot.steering=steer*1.5
    18 while True:
--> 19     LF.run(callback=drive)

/usr/local/lib/python3.6/dist-packages/pop/Pilot.py in run(self, value, callback)
    1816
    1817         if callback is not None:
-> 1818             callback(result)
    1819
    1820         return result

<ipython-input-9-3f7aae61c1a9> in drive(value)
      3 bot.setSpeed (40)
      4 def drive(value):
----> 5     bot.forward()
      6
      7     steer=value['x']

/usr/local/lib/python3.6/dist-packages/pop/Pilot.py in forward(self, speed)
    910         self.speed=speed
    911
-> 912         self.drv.drive(self.drv.steer, self.speed)
    913
    914     def backward(self, speed=None):

/usr/local/lib/python3.6/dist-packages/pop/Pilot.py in drive(self, steer, speed)
    789         w3*=rate*self.speed
    790
-> 791         self.whl(1,w1)
    792         self.whl(2,w2)
    793         self.whl(3,w3)

/usr/local/lib/python3.6/dist-packages/pop/CAN.py in wheel(self, id, value)
    97         self._wheels[4]=0
    98         self._wheels[5]=0
--> 99         time.sleep(0.01)
    100         self.can.write(self.MOTOR_CONTROL,self._wheels)
    101

```

KeyboardInterrupt:

In [ ]:

In [ ]: