

**Input:**



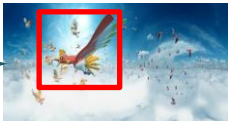
Panoramic  
Video  
**Input:**



HM Scan-path  
ground-truth

**Environment**

**FoV Extractor**



**Reward Estimator**

Equation (2)

Equation (3)

$\alpha_t$   $\nu_t$   
**Action**

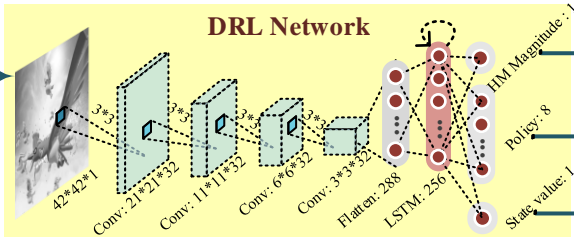
$O_t$   
**Observation**

$r_t^\alpha$   $r_t^\nu$   
**Reward**

**HM Scan-path Predictor**

Add noise and generate action

**DRL Network**



**Actions:** Predicted  
HM Scan-path



selected

**Optimizer**

Update global shared  
parameter vectors via  
accumulating gradient

Equation (4)

Equation (5)

Equation (6)