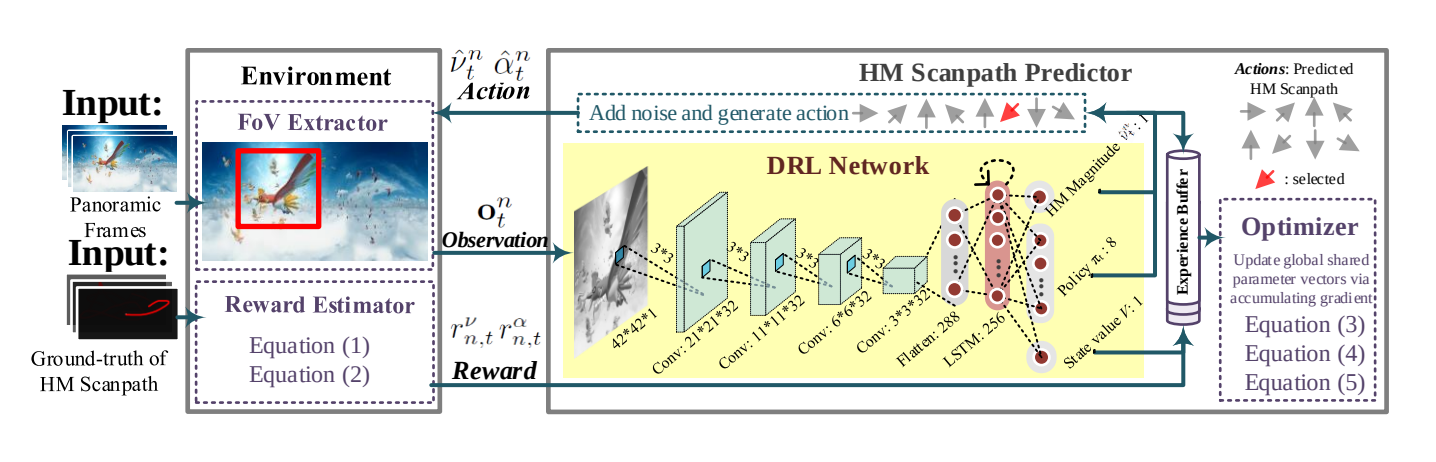
Input:
Panoramic Frames
Input:
Ground-truth of HM Scanpath
Environment
FoV Extractor
Reward Estimator
Equation (1)
Equation (2)
$\hat{\nu}_t^n$ $\hat{\alpha}_t^n$
Action
$\mathbf{o}_t^n$
Observation
$r_{n,t}^{\nu}$ $r_{n,t}^{\alpha}$
Reward
HM Scanpath Predictor
Add noise and generate action
DRL Network
42*42*1
Conv: 21*21*32
Conv: 11*11*32
Conv: 6*6*32
Conv: 3*3*32
Flatten: 288
LSTM: 256
HM Magnitude ν_t^n: 1
Policy π_t: 8
State value V_t: 1
Experience Buffer
Actions: Predicted HM Scanpath
: selected
Optimizer
Update global shared parameter vectors via accumulating gradient
Equation (3)
Equation (4)
Equation (5)