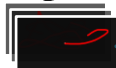


Input:



Panoramic
Frames

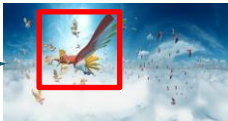
Input:



Ground-truth of
HM Scan-path

Environment

FoV Extractor



Reward Estimator

Equation (1)

Equation (2)

\hat{V}_t^n $\hat{\alpha}_t^n$
Action

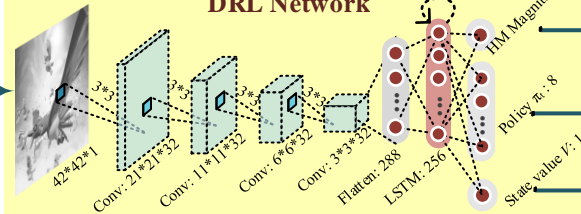
\mathbf{O}_t^n
Observation

$r_{n,t}^\nu$ $r_{n,t}^\alpha$
Reward

HM Scan-path Predictor

Add noise and generate action

DRL Network



HM Magnitude \hat{V}_t^n

Policy π_t

State value V_t

Actions: Predicted
HM Scan-path



\blacktriangleleft : selected

Optimizer

Update global shared
parameter vectors via
accumulating gradient

Equation (3)

Equation (4)

Equation (5)