e: ▸ AAIC ▸ SelfDrivingCar ▸ run_dataset.py

```
import cv2
import csv

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

smoothed_angle = 0
in_file = open('test-predictions.csv', 'r')

csv_reader = csv.reader(in_file)

header = None
cv2.imshow("steering wheel", steering_img)

for row in csv_reader:
    if header == None:
        header = row
        continue
    if(cv2.waitKey(12) == ord('q')): break
    car_img = cv2.imread(row[0])
    cv2.imshow('frame', car_img)
    degrees = float(row[1])

    diff = degrees - smoothed_angle

    if diff != 0:
        smoothed_angle += 0.2 * pow(abs(diff), 2.0 / 3.0) * (diff) / abs(diff)
    M = cv2.getRotationMatrix2D((cols/2,rows/2),-smoothed_angle,1)
    dst = cv2.warpAffine(steering_img,M,(cols,rows))
    cv2.imshow("steering wheel", dst)

cv2.destroyAllWindows()

```