SELF DRIVING CAR NANODEGREE

Project 3 : Behavior Cloning

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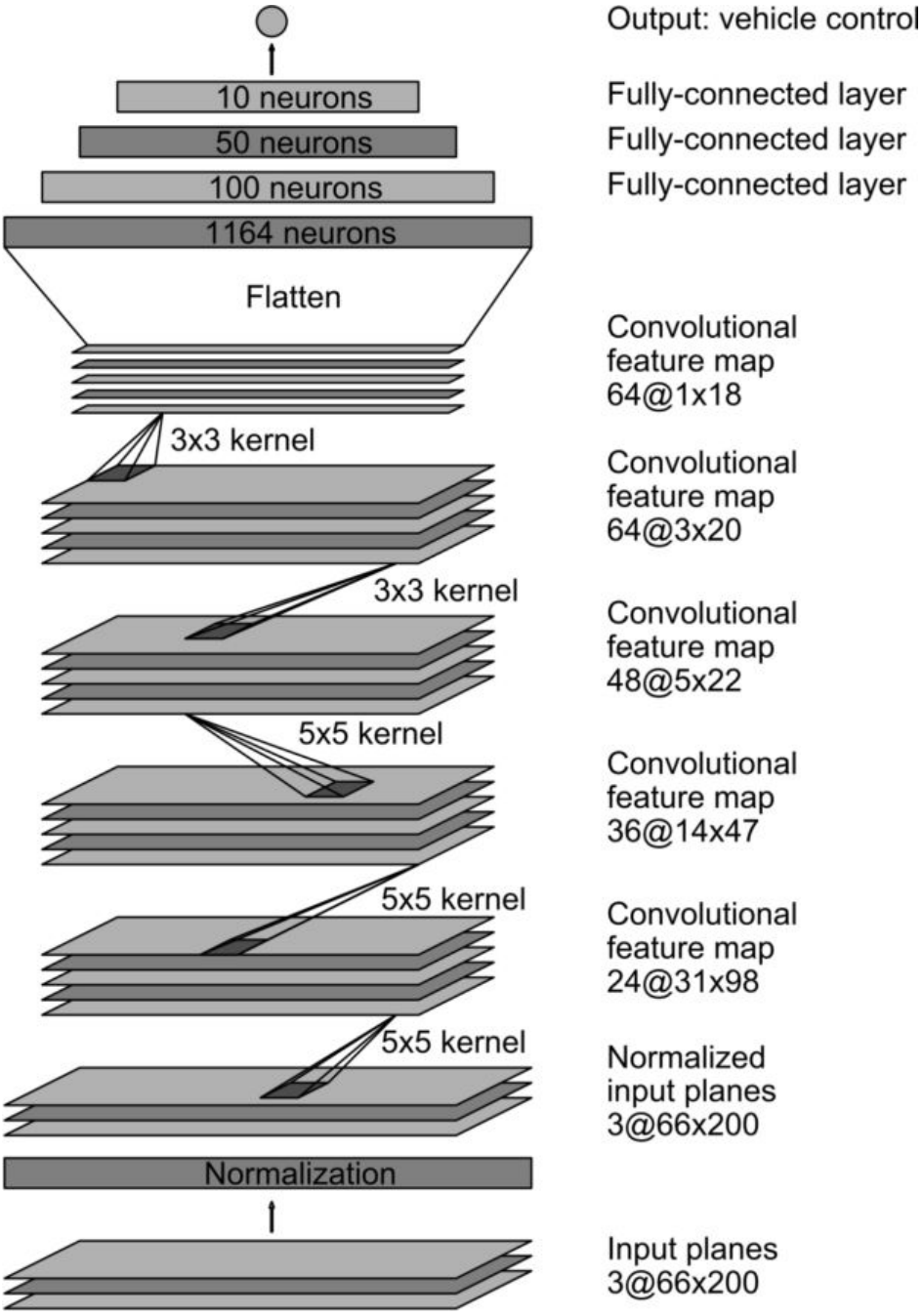
Step 1 :Collecting Data.

With the help of simulator I drove around 7-8 Laps and the 3 Cameras attached recorded the data as images from their respective angles.

Step2 : Building the model.

I have used Keras as my framework with Tensorflow as its backend.
Before building the Model I need to feed my data in my Neural Network and thus have uss load_dataset() for the Purpose.
Below Shows the NVIDIA architecture



I have implemented the Same Architecture but have added dropout after the 5th convolution to reduce overfitting and then allowed it to go to fully Connected Layers.

For minimizing error I have used Adam Optimizer because no need to change Learning Rate manually.

As The number of Epoch Increasing the loss started varying highly.