

Going Deeper: Autonomous Steering with Neural Memory Networks

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1. Supplementary Material

Figures 1, 2 and 3 further demonstrate the performance of the proposed approach by illustrating its performance in various challenging conditions. For all sequences we compare to the baseline of [1].

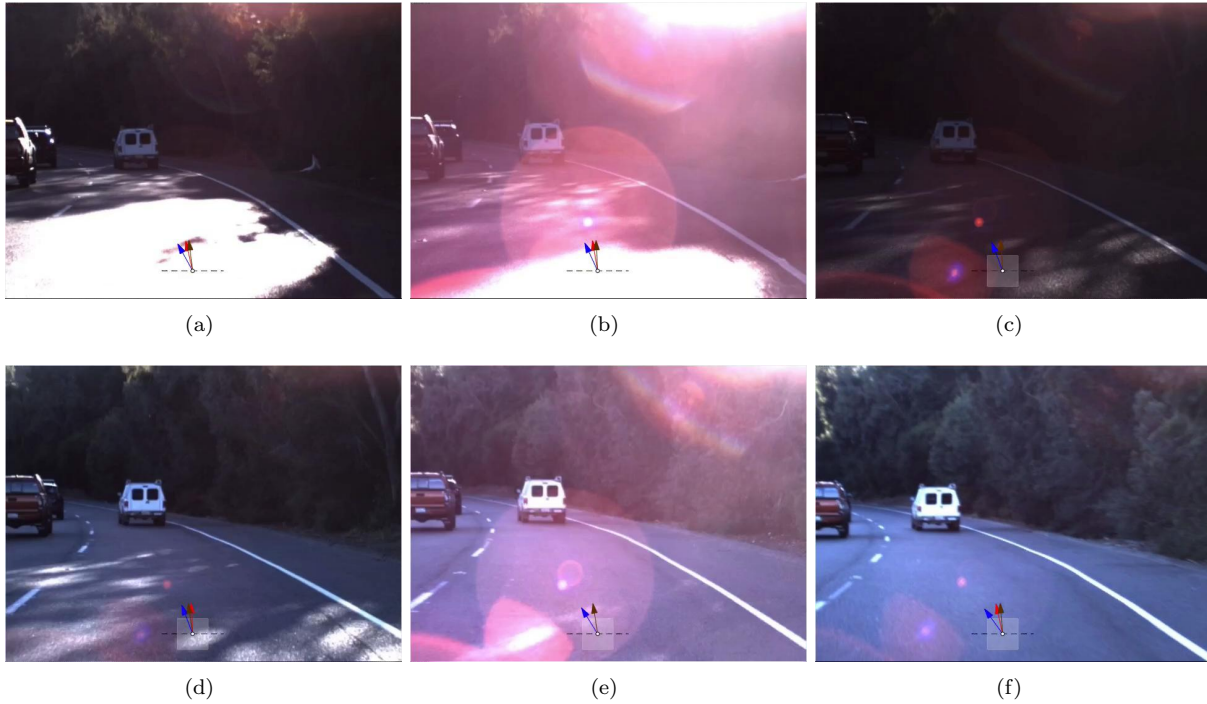


Figure 1. Different illumination conditions where the illumination conditions vary from direct sunlight to shadows, to normal within few seconds. Blue: Ground Truth; Red: Proposed; Brown: Baseline [1]

References

- [1] H. Xu, Y. Gao, F. Yu, and T. Darrell. End-to-end learning of driving models from large-scale video datasets. *arXiv preprint arXiv:1612.01079*, 2016. 1, 2

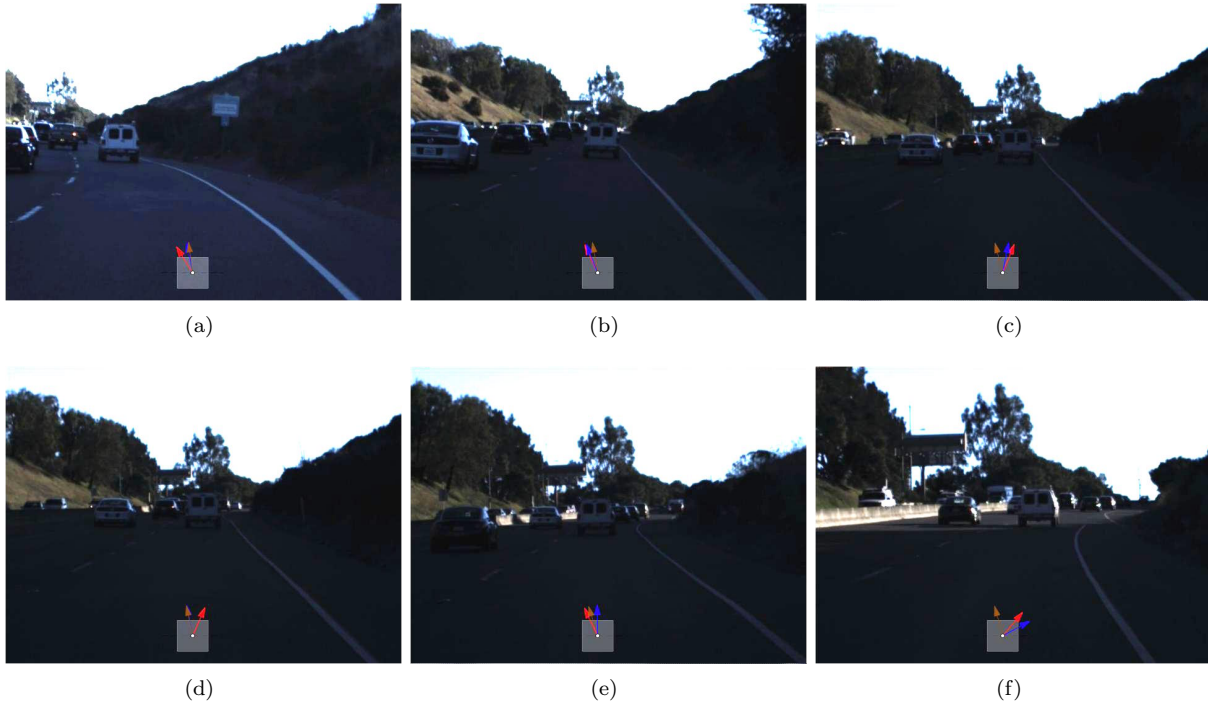


Figure 2. Entering a divided highway from an entrance ramp: Blue: Ground Truth; Red: Proposed; Brown: Baseline [1]



Figure 3. Giving way to the merging traffic in the front: Blue: Ground Truth; Red: Proposed; Brown: Baseline [1]