To train the network, video footage from the camera was broken down into about 10 images per second, which were sorted into network output classes based on what was in the image and how the car should react. Some images included directive signs, while others just contained the natural features of the empty hallway. An estimated 6,000 images were used to train and test the network.

Since we need to put additional components on the car, we did 3D printing designs to combine the individual parts into one piece.