DAIT Project

Trajectory Preduiction for Human-Human Interaction

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23.05.2018

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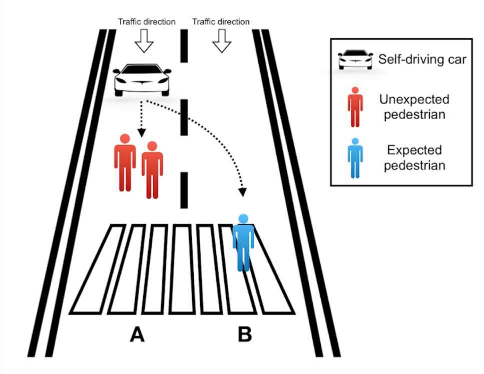
Introduction

Introduction

Motivation:

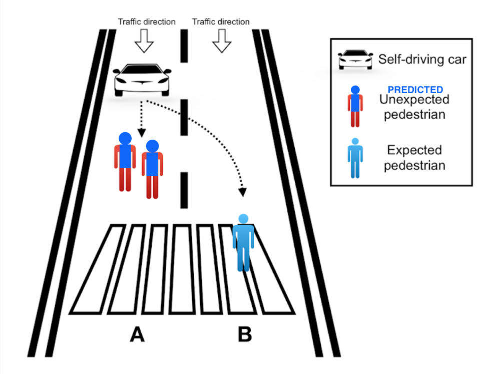
- Trajectory prediction is crucial for improving autonomous vehicles behaviour



Introduction

Motivation:

- Trajectory prediction is crucial for improving autonomous vehicles behaviour
- Could avoid situations seen in the ethical lectures



Previous work

Some models have been developed for trajectory prediction:

- Social forces
- Social LSTM
- Discrete choice model

We chose to develop two different models:

- One CNN
- One LSTM

The parameters of both models are standard.

Preprocessing and Postprocessing

Preprocessing

The preprocessing step is crucial in our models

- What we have: files with pedestrians id, frame number and coordinates
- What we want: future coordinates

Each trajectories are divided in two (two sets of 10 x and y coordinates):

- Training coordinates
- Ground truth
- We want to predict a sequence of 10 x and y coordinates such that they are close to the ground truth

Preprocessing

The preprocessing is divided in 4 steps:

1. We isolate each trajectory along with his interaction, that is the other trajectories that are around within the same frames
2. We normalize the trajectories such that the first point is at $(0, 0)$ and the second is at $(0, y_1)$
3. We calculate axis velocities V_x and V_y
4. For each frame, if there is a interacting pedestrian we add its coordinates and speed otherwise zeros are added

Finally our inputs have the following shape: $[10, N, 4 * N_{inter}]$, with

- 10: sequence length
- N: The number of data
- $4 * N_{inter}$: 4 (being the x and y coordinates and V_x and V_y velocities) times the number of pedestrians interacting with the one of interest.

Outputs shape

- The models can predict either coordinate or speed or both
- We test our two models for 4 different cases

The four different cases are:

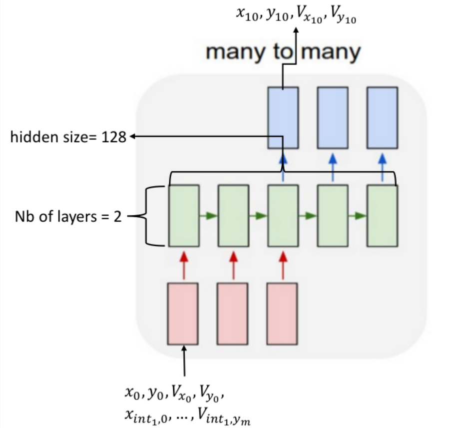
1. Predict coordinates with loss defines as $L_1 = (X - X_{pred})^2$ with $X = [x, y]$
2. Predict speeds with loss defines as $L_2 = (V - V_{pred})^2$ with $V = [V_x, V_y]$
3. Predict both coordinates and speeds with loss defines as $L = L_1 + L_2$
4. Predict both coordinates and speeds with loss defines as $L = L_1 + L_2 + L_3$, with $L_3 = (X - X_{t-1} + V_t * 0.4)^2$

The fourth case ensure that coordinates and speeds are not predicted independently.

Models

Define CNN

LSTM



Inputs: sequence of coordinates and velocities of the trajectory of interest and of the interacting trajectories

Outputs: sequence of predicted coordinates and velocities for the trajectory of interest

Results

Results: Introduction

To calculate the correctness of the prediction two indicators are used:

1. The final displacement error: $e_{fin} = \sqrt{(X_n - X_{pred,n})^2}$
2. The mean displacement error: $e_{fin} = \sqrt{\frac{\sum_{i=0}^{n}(X_{gt,i} - X_{pred,i})^2}{(n)}}$

Depending on the inputs two ways are possible to find the predicted coordinates:

1. If the coordinates are predicted: directly use them
2. If the velocities are predicted: $X_t = X_{t-1} + V_t \cdot 0.4$, with 0.4 the time between two frames in seconds

Results: LSTM

	Model 1			Model 2			Model 3			Model 4		
	Traj Type			Traj type			Traj type			Traj type		
	1	2	3	1	2	3	1	2	3	1	2	3
Mean disp. L2												
Final disp. L2												

Representation