DAIT Project

Trajectory Preduiction for Human-Human Interaction

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EPFL

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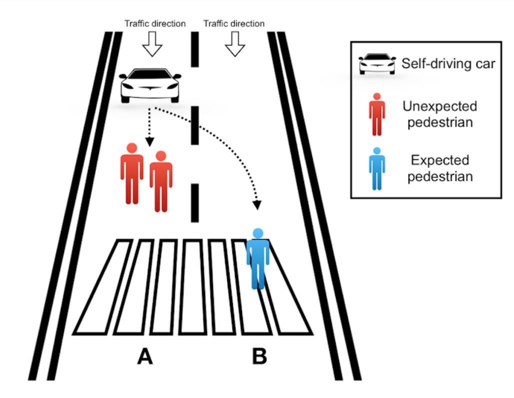
Introduction

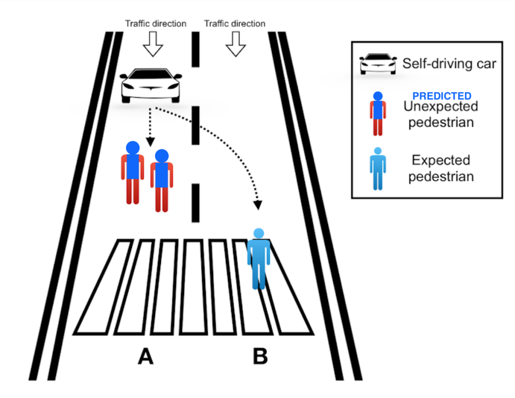
Introduction

- Trajectory prediction is crucial for improving autonomous vehicles behaviour



Introduction

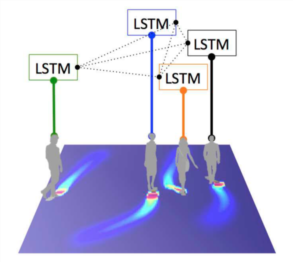
- Trajectory prediction is crucial for improving autonomous vehicles behaviour
- Could avoid situations seen in the ethical lectures



Previous work Social LSTM : Human Trajectory Prediction in Crowded Spaces

In their project, they used different components to make the structure:

- One LSTM per pedestrian
- Social Pooling
- Prediction per frame



Images from Social LSTM:Human Trajectory Prediction in Crowded Spaces and courses lecture

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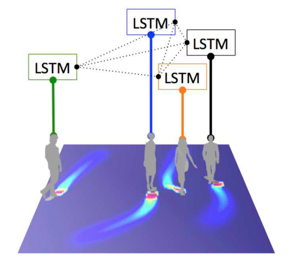
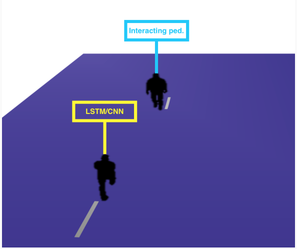


In our project we only use:

- One CNN, or one LSTM
- Prediction per pedestrian



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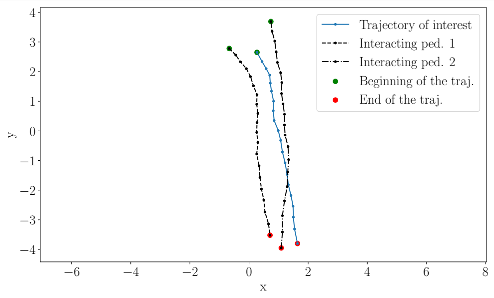
Data

The preprocessing is divided in 4 steps:

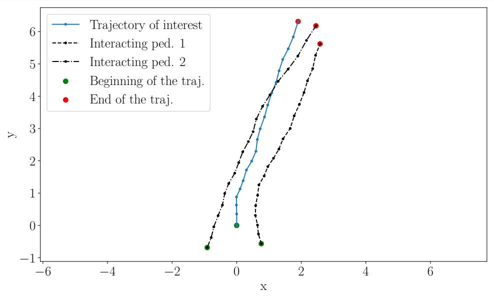
1. We isolate each trajectory along with his interaction, that is the other trajectories that are around within the same frames



Pre-processing

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 $(0, y_1)$



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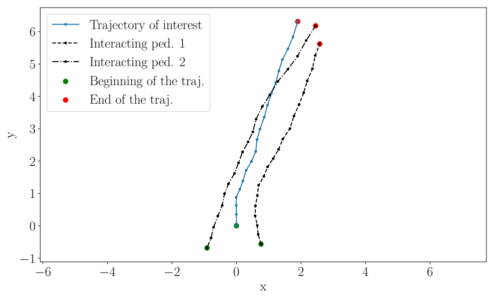

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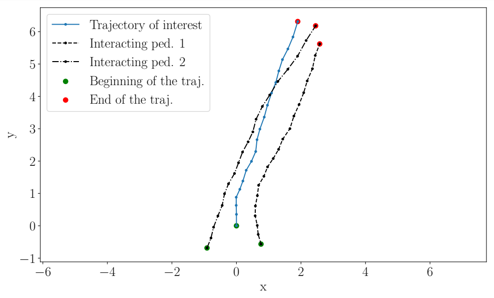
4. For each frame, if there is a interacting pedestrian we add its coordinates and speed otherwise zeros are added



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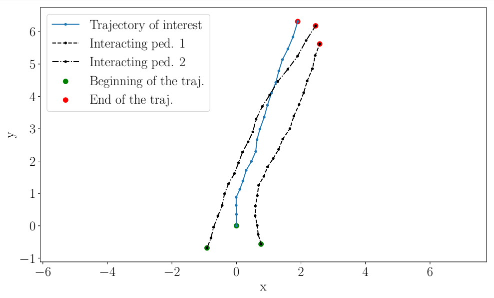
4. For each frame, if there is a interacting pedestrian we add its coordinates and speed otherwise zeros are added
5. Data augmentation (flip and add noise) cf. last slide



Data

We have a file with:

- Pedestrians ID
- Frame number
- Twenty sets of x and y coordinates per pedestrian

Frame Number	ID	x	y	V_x	V_y
$\vdots$	$\vdots$	$\vdots$	$\vdots$	$\vdots$	$\vdots$

Data

We have a file with:

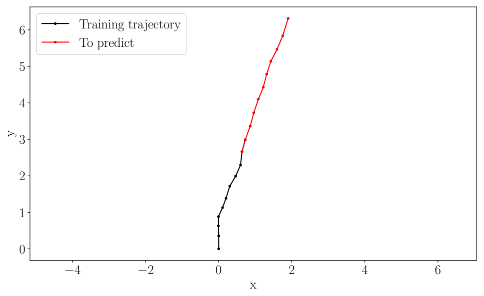
- Pedestrians ID
- Frame number
- Twenty sets of x and y coordinates per pedestrian

We want :

- Train on the 10 first coordinates
- Predict the next 10

Frame Number	ID	x	y	V_x	V_y
$\vdots$	$\vdots$	$\vdots$	$\vdots$	$\vdots$	$\vdots$

Example of trajectory to predict



Outputs structure

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.

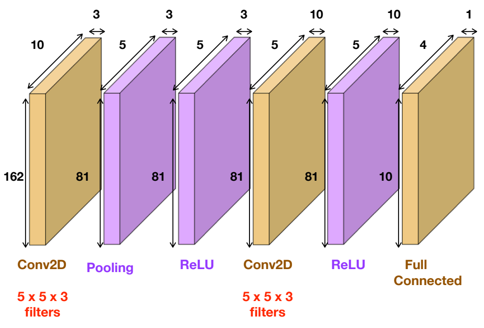
The four different cases are:

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.

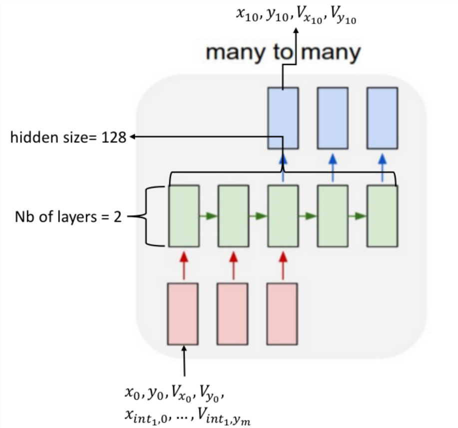
Models

CNN



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

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

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 for both models:

- 3 Types of trajectory defined: Static, linear and non-linear trajectories
- Mean and Final displacements

Results

Linear prediction results:

- Type 1: $Mean = 0.141$, $Final = 0.322$
- Type 2: $Mean = 0.541$, $Final = 0.93$
- Type 3: $Mean = 0.651$, $Final = 1.457$
- Total: $Mean = 0.512$, $Final = 0.982$

[]

		CNN				LSTM			
		Type 1	**Type 2**	**Type 3**	**Total**	**Type 1**	**Type 2**	**Type 3**	**Total**
Coord.	**Mean**	4.696	5.144	4.674		1.16	0.768	0.817	0.837
	Final	10.246	7.009	10.501		1.269	0.911	1.087	1.011
Speed	**Mean**	0.567	5.133	1.911		0.742	0.397	0.448	**0.461**
	Final	0.77	6.971	3.882		1.433	0.716	0.874	**0.863**
2 Loss	**Mean**	1.269	5.134	1.762		0.519	0.484	0.568	0.511
	Final	2.727	6.978	3.546		0.979	0.871	1.093	0.946
3 Loss	**Mean**	0.549	5.135	3.829		0.537	0.473	0.576	0.51
	Final	0.758	6.983	4.962		0.992	0.86	1.125	0.95

Discussion

Representation

Representation

Dynamic Representation

Discussion