

# Report Template

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## ABSTRACT

Pedestrians trajectories prediction has become a popular topic in recent years. Many approaches can be used to accomplish the prediction, including deterministic and non-deterministic ways. In this report we make research and discussion about how to use the a non-deterministic method i.e. deep learning to solve the prediction problem. The algorithms we are going to use is the combination of SocialGAN and InfoGAN. First we train a model by the adopted algorithms. Second, during the research, we propose our research questions and try to answer it in the report.

## INTRODUCTION

Systems and electronic devices that using pedestrian trajectories prediction can be found everywhere in our daily life, e.g., service robots, automatic drive and city planning etc. Hence, it is useful and important to make predictions about pedestrians movement. Many researches proposed miscellaneous approaches that tackle this problem. Helbing and Molnar [6] propose the Social Force model. Yi [8] introduces factor of stationary group to modeling of pedestrians trajectories with an energy map. The aforementioned ways are deterministic ways for prediction, they can not utilize the valuable information in the trajectories data.

Over the last few years, following the widely usage of machine learning and deep learning, researchers use various neural networks to tackle the trajectories prediction problem. Zhou et al. [9] build a linear dynamic systems, applying Expectation Maximization (EM) algorithm to estimate parameters, to learn motion patterns in crowded scenes. In Alth   [2] proposes a method that predict the trajectory on highway using Long Short-Term Memory (LSTM). Alahi et al. [1] gives a sequence model based on LSTM as well as a social pooling which aggregates the human-human interaction in a scene.

However, these approaches mentioned previously learn only the pattern of human motion from data. Predicting human trajectory is a complex task. This is because both internal and external stimuli, such as intentions and other directly or indirectly observable influences, can affect human motion, as mentioned in the survey [7]. In addition to the location, which is usually recorded in the dataset, there are many factors that are not explicitly recorded in the dataset, such as speed, direction, or even not recorded, such as route and human intent. Recent researches have shown that Generative Adversarial Network (GAN) can better capture these

uncertainties with latent space and thus naturally preserve multi-modality. Gupta et al. [5] used GAN and a Pooling Module to predict socially acceptable trajectories and found that certain directions in the latent space are related to direction and velocity. What is more, The study of Amirian et al. [3] has shown that InfoGAN, an information-theoretic extension to the Generative Adversarial Network [4], partly improves the performance on commonly used datasets that have the largest variance in the prediction distribution, while still leaving some room for improvement.

Even though these researches give various effective models that fulfill the prediction task and attempt to encompass hidden aspects that influence the trajectory, they have not disentangled these factors in the latent space. If we know the factors that affect pedestrians trajectory and apply these factors in specific scenarios. We can obtain better performance of prediction on various distributed datasets and to mitigate the limitations of the observed data. Therefore, we decide to consider the hidden factors behind different datasets.

In this study, we focus on what factors we can obtain that influence human trajectories and try to develop a model that can be controlled by these factors. we assume that different datasets have different static environments and so the data in a dataset share some specific common features. We consider three factors: obstacles (obstacles information such as the presence of static obstacles and the coordinates), maps (geometry and topology), and semantics (environment semantics such as no-go-zones, crosswalks, side-walks, or traffic lights) in static environments, which are denoted by the survey [7]. We propose to develop a conditional generation model that is controlled by factor  $c$  to have different static environments. We demonstrate that human movement is influenced by these three factors we consider in a static environment, and so with inputting different factors in static environments, our model can achieve better performance on different datasets.

## 1 PROBLEM STATEMENT

In this paper, our goal is to develop a controllable generative model to predict pedestrian trajectories. Consider the problem of predicting the future trajectory of each pedestrian. Let  $(x_i^t, y_i^t)$  denote the position of the  $i$  pedestrian at time  $t$ , and a sequence of coordinates  $[(x_i^t, y_i^t), (x_i^{t+1}, y_i^{t+1}), \dots, (x_i^{t+n}, y_i^{t+n})]$  denote the trajectory of pedestrians from time  $t$  to  $t + n$ .

Given the observed trajectory of  $n_{obs}$  steps  $X_i^t = [(x_i^t, y_i^t), (x_i^{t+1}, y_i^{t+1}), \dots, (x_i^{t+n_{obs}}, y_i^{t+n_{obs}})]$ , with certain condition  $c$  and random variable  $z$ , we want to fit a function to generate the prediction of trajectory for the next  $n_{pred}$  steps  $Y_i^t = [(x_i^{t+n_{obs}+1}, y_i^{t+n_{obs}+1}),$

$$(x_i^{t+n_{obs}+2}, y_i^{t+n_{obs}+2}), \dots, (x_i^{t+n_{obs}+n_{pred}}, y_i^{t+n_{obs}+n_{pred}})]. \text{ That is}$$

$$Y_i^t = f(X_i^t | c, z)$$

The prediction  $Y_i^t$  is conditioned on the vector  $c$ , where consist of  $(c_1, c_2, c_3)$ . So we can control the factors of obstacles, maps and semantics respectively. These factors might vary over time.

## Appendices

If your work needs an appendix, add it before the “\end{document}” command at the conclusion of your source document.

Start the appendix with the “appendix” command:

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\appendix
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and note that in the appendix, sections are lettered, not numbered. This document has two appendices, demonstrating the section and subsection identification method.

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## A RESEARCH METHODS (REMOVE IF NOT USED)

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## B ONLINE RESOURCES

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