

Environment-Aware Pedestrian Trajectory Prediction for Autonomous Driving

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Content

- Motivation
- Related work
- Problem
- My approach
 - Data loader
 - Network architecture
 - Future work



Motivation

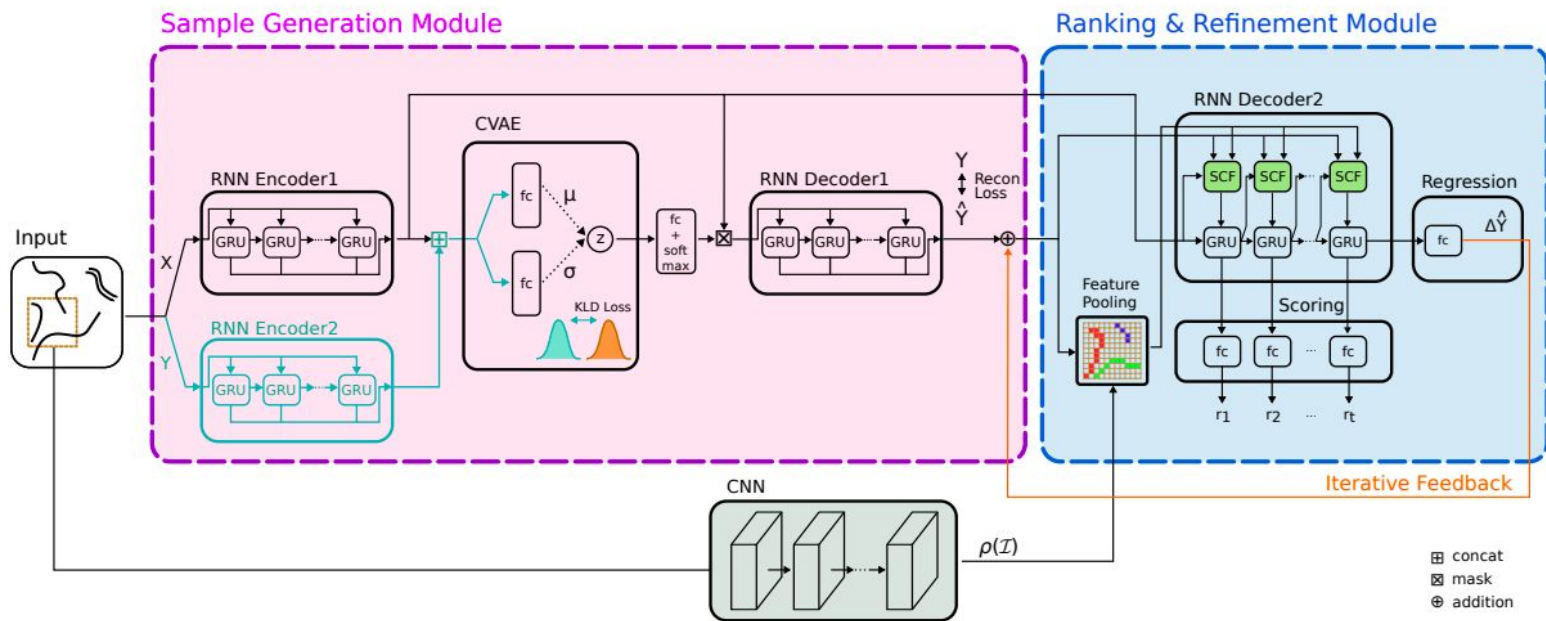
- Autonomous driving is growing!
- Concerns
 - Pedestrian safety
 - Efficient/safe driving



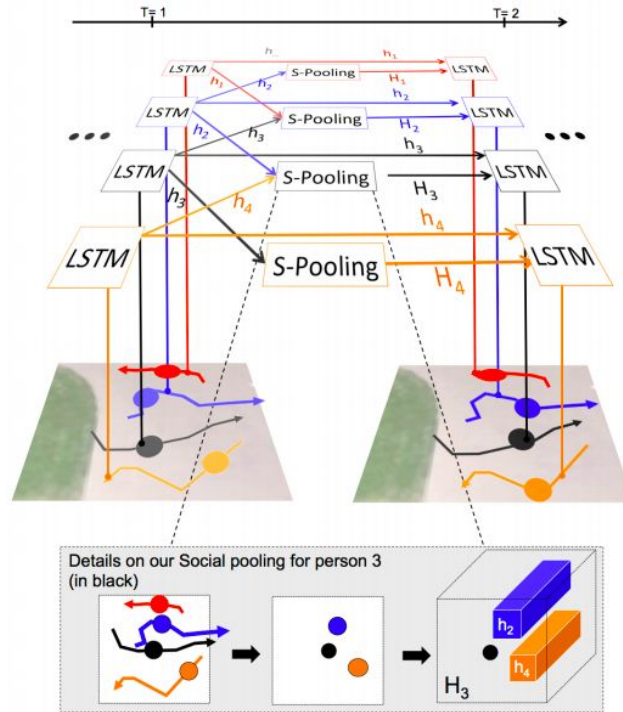
Related Work: Multimodal Future Prediction



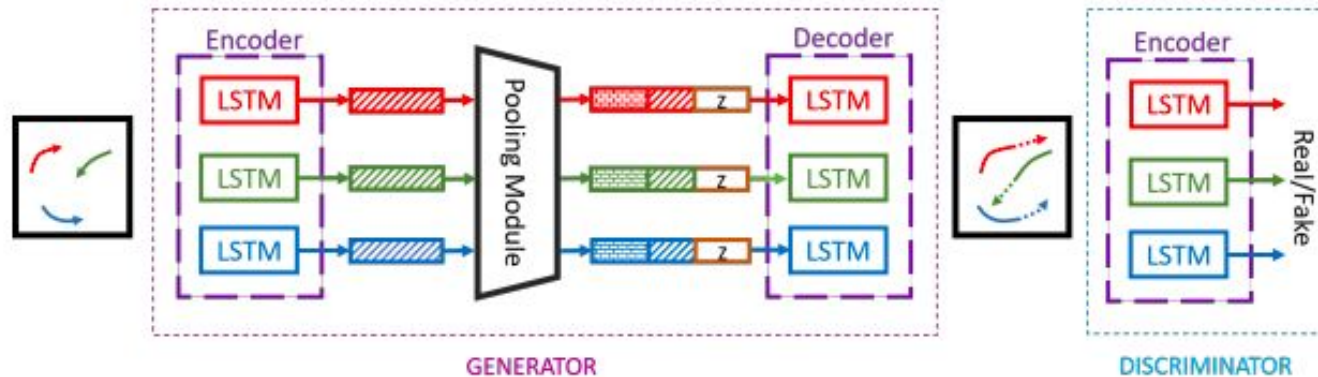
Related Work (cont.): DESIRE



Related Work (cont.): Social LSTM



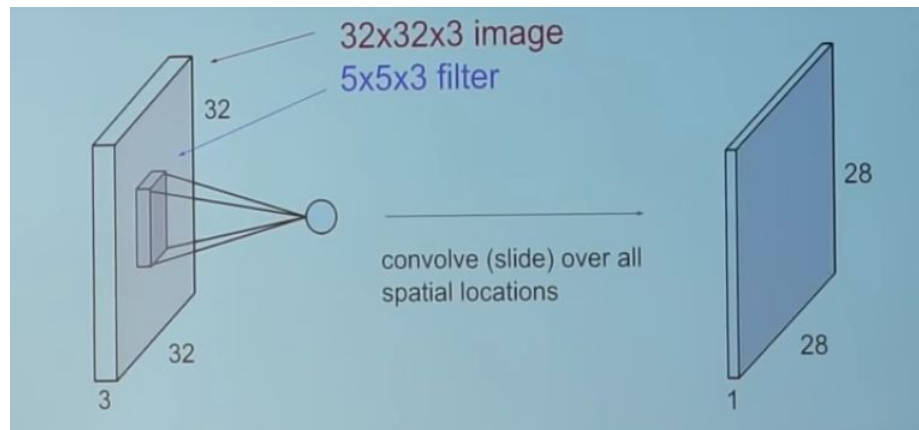
Related Work (cont.): Social GAN





Problem

- Complex architectures
 - CNN/RNN
- Location-awareness
 - Location bias map
- Versatility
 - Multiple agents



Our Datasets (2 environments)

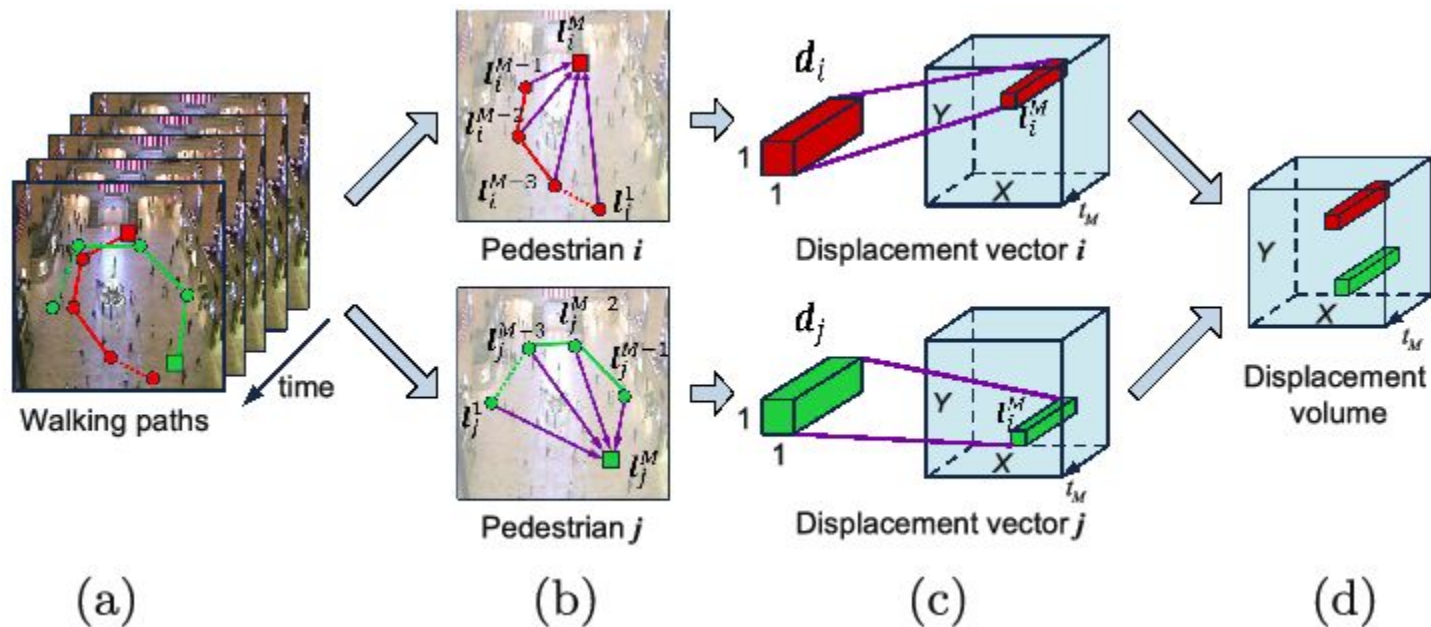


[Collected from ETH main building, Zurich, by Stefano Pellegrini and Andreas Ess in 2009]

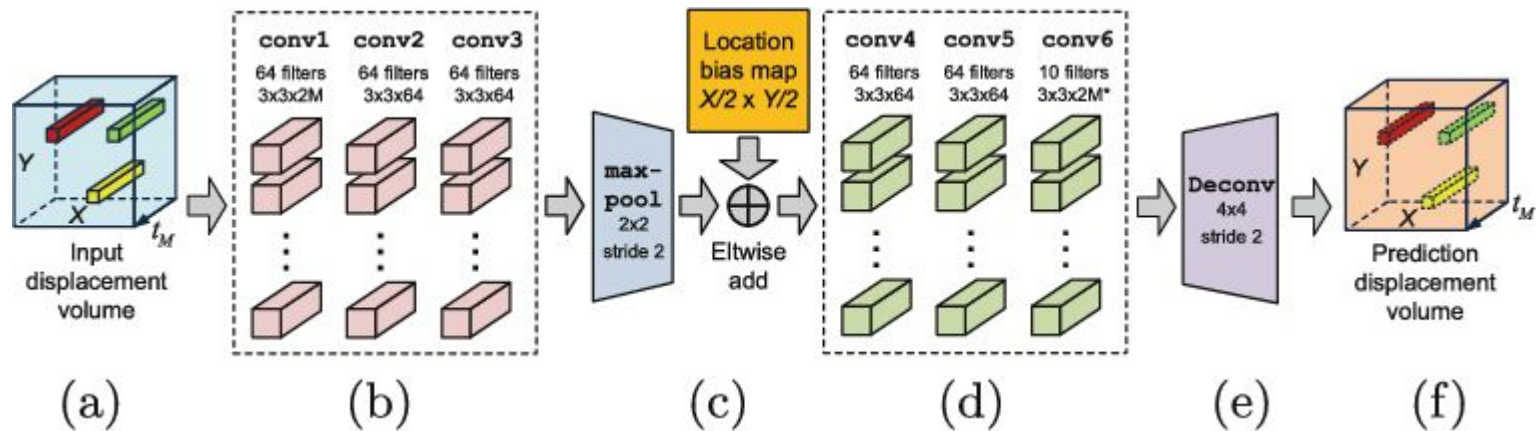


[Collected from hotel in Bahnhofstr, Zurich, by Stefano Pellegrini and Andreas Ess in 2009]

Data Loader



Architecture





Status/Future Work

- Location bias map improvements
 - Train on multiple locations

- Train on multiple agents
 - Pedestrians, cars, cyclists, scooters

- Multimodal approach





Special thanks to...

- My mentor: Dr. Igor Gilitschenski
- Dr. Slava Gerovitch
- MIT PRIMES + CSAIL

The slide features a solid orange background. In the top-left corner, there are three vertical bars of varying heights, each composed of several overlapping semi-transparent circles. A similar set of four vertical bars is located in the bottom-right corner, also made of overlapping semi-transparent circles.

Thank you for listening!
Questions?