# LYLES SCHOOL





Big Idea: Predict future trajectories of heterogeneous road users based on their observed trajectories and interactions. **?**• 

![](_page_0_Figure_8.jpeg)

![](_page_0_Figure_9.jpeg)

Evaluation Metric	Prediction Horizon (s)	Social Force	Seq2Seq	Social- LSTM	ConvSP- LSTM	ST-GCN- Seq2Seq
RMSE (m)	0.5	0.406	0.672	0.256	0.267	0.196
	1	0.661	1.082	0.322	0.343	0.234
	1.5	0.783	1.287	0.359	0.385	0.272
	2	1.022	1.704	0.447	0.481	0.341
	2.5	1.140	1.916	0.498	0.538	0.377
	3	1.371	2.348	0.638	0.706	0.452

# **Scenario 1 (Pedestrian-Motorist Interaction):**

![](_page_0_Picture_17.jpeg)

# Scenario 2 (Hybrid Interactions):

![](_page_0_Picture_19.jpeg)

## **1.** An open-sourced large-scale trajectory dataset.

### **Smart interaction at crosswalks:** 2.

Ο surrounding road users in real time.

### **Design of an intelligent tracking system at crosswalks:** 3.

- Ο
- Ο motion predictions.

![](_page_0_Picture_26.jpeg)

![](_page_0_Picture_27.jpeg)

![](_page_0_Picture_28.jpeg)

### CENTER FOR CONNECTED AND AUTOMATED TRANSPORTATION

### **Model Comparisons**

### Experiments

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Acceleration
Deceleration

## Conclusions

Notify a subject road user of motion predictions of

The appropriate sensor (Miovision) can be deployed to capture the spatial-temporal positions of each road user. Cellphone applications can be developed for tracking and