

Motivation

Behavioural Planning

- High-level decisions: lane, stop or go
- In interaction with other drivers

Reinforcement Learning

Optimal Control Objective

$$Q^*(s, a) \stackrel{\text{def}}{=} \max_{\pi} \mathbb{E} \left[\sum_{t=0}^{\infty} \gamma^t R(s_t, a_t) \mid s_0=s, a_0=a \right]$$

Bellman Optimality Equation and DQN Algorithm

$$Q^*(s, a) = \mathbb{E}_{s' \sim P(s'|s, a)} \max_{a' \in A} [R(s, a) + \gamma Q^*(s', a')]$$

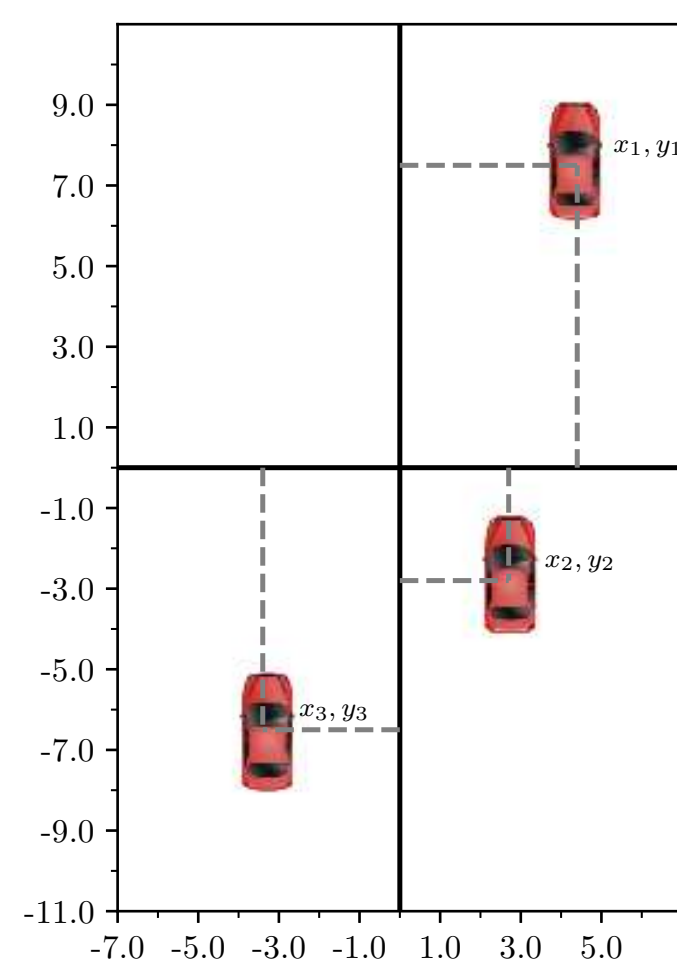
State Representation

Representing social interactions

A joint state s of $N + 1$ observed vehicles

$$s = (s_i)_{i \in [0, N]}$$

$$s_i = [x_i \ y_i \ v_i^x \ v_i^y \ \cos \psi_i \ \sin \psi_i]^T$$



List of features representation

Issues related to function approximation

1. Variable size

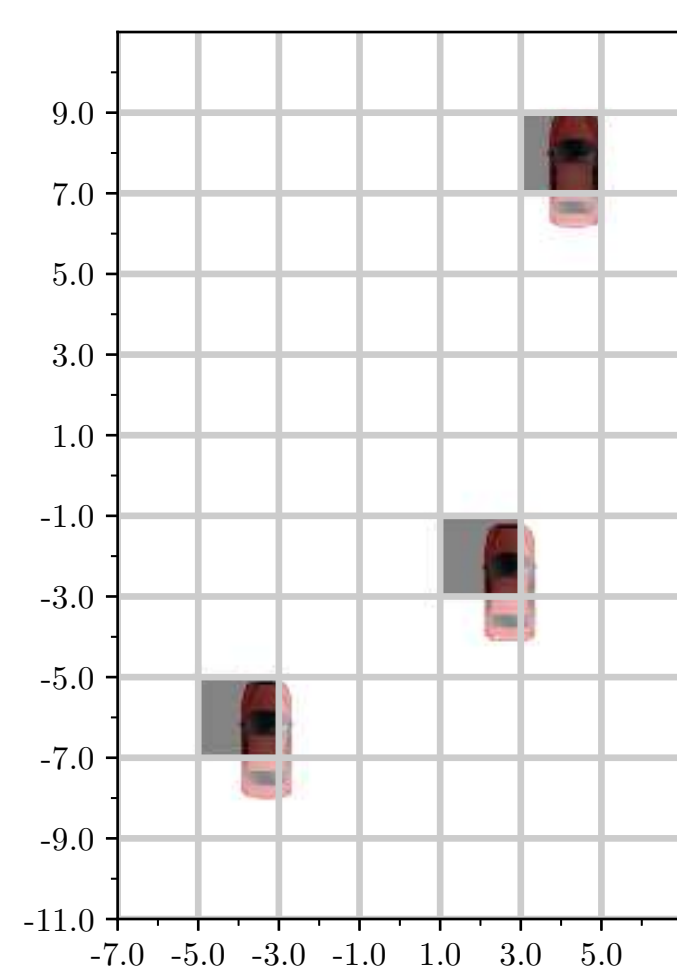
↳ usual models accept fixed-size inputs

2. Sensitivity to the ordering

↳ we want the policy to be permutation-invariant:

$$\forall \tau \in \mathfrak{S}_N, \quad \pi(\cdot | (s_0, s_1, \dots, s_N)) = \pi(\cdot | (s_0, s_{\tau(1)}, \dots, s_{\tau(N)}))$$

A common solution



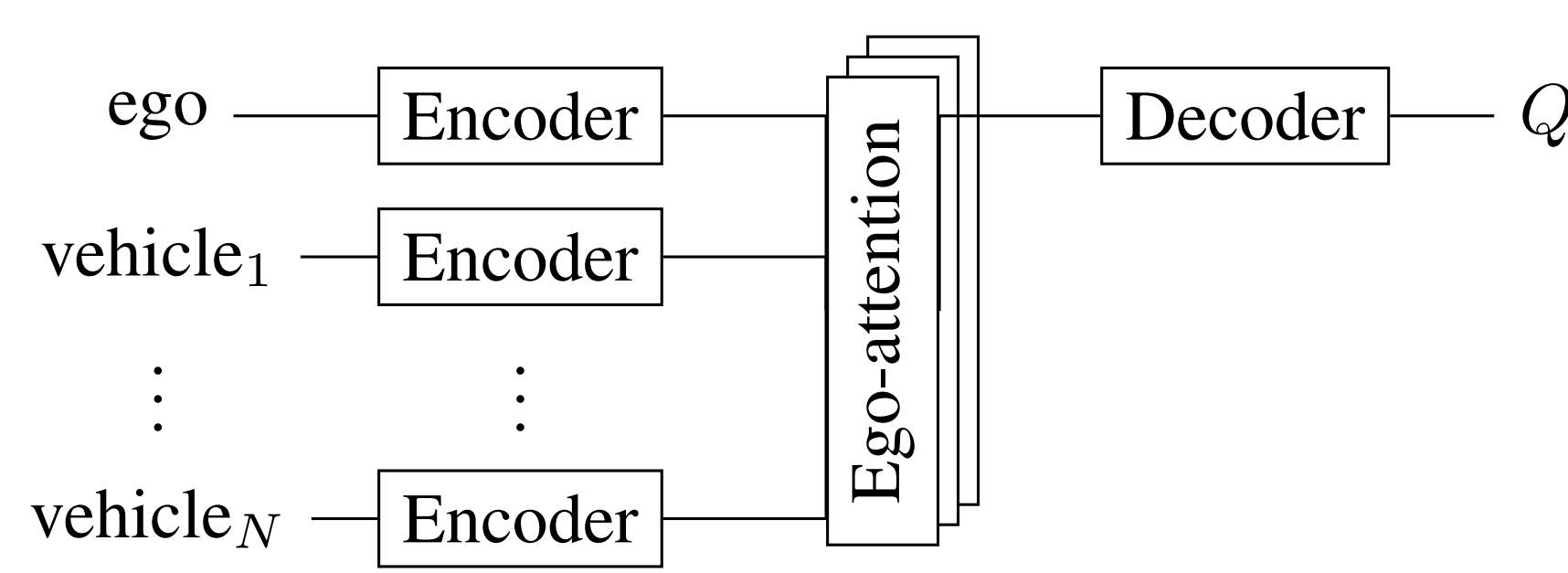
Occupancy grid representation

- ✓ Fixed-size
- ✓ Does not depend on an ordering
- ✗ Suffers from an accuracy / size tradeoff

Acknowledgements

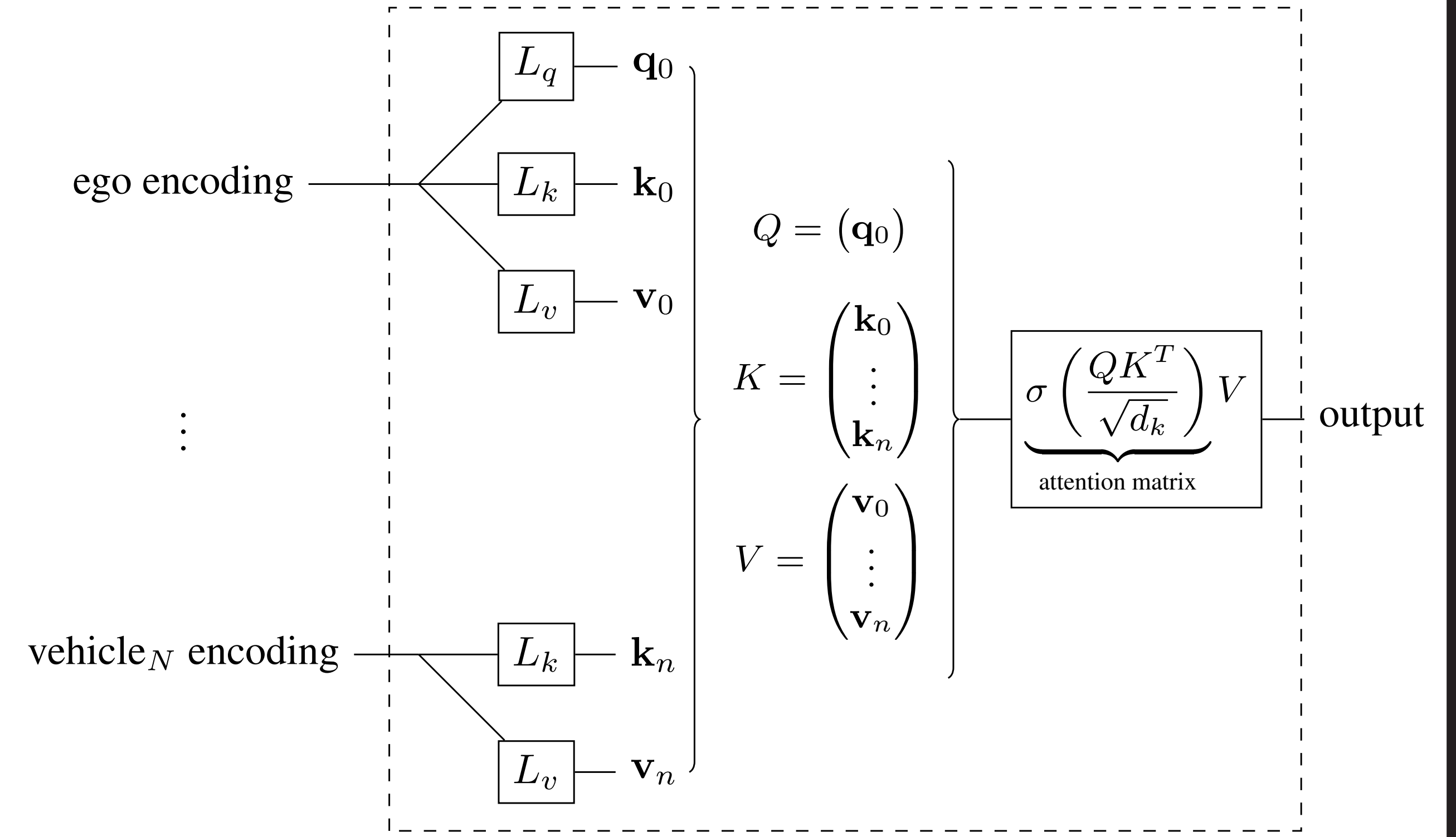
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Model Architecture



Model architecture

- ✓ Inputs can have a variable size
- ✓ Based on a dot product
 - ↳ permutation-invariant
- ✓ Compact size with no accuracy loss



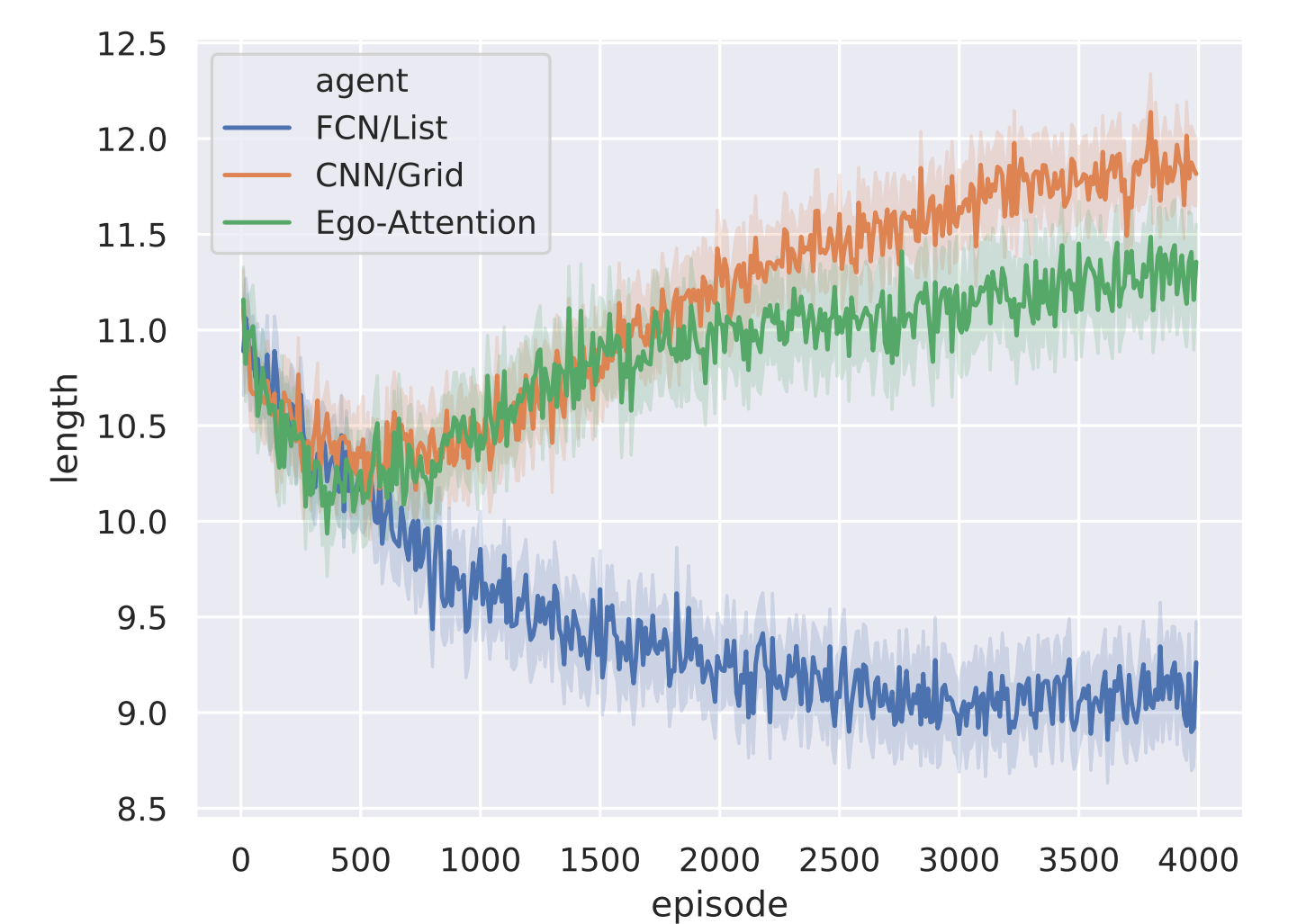
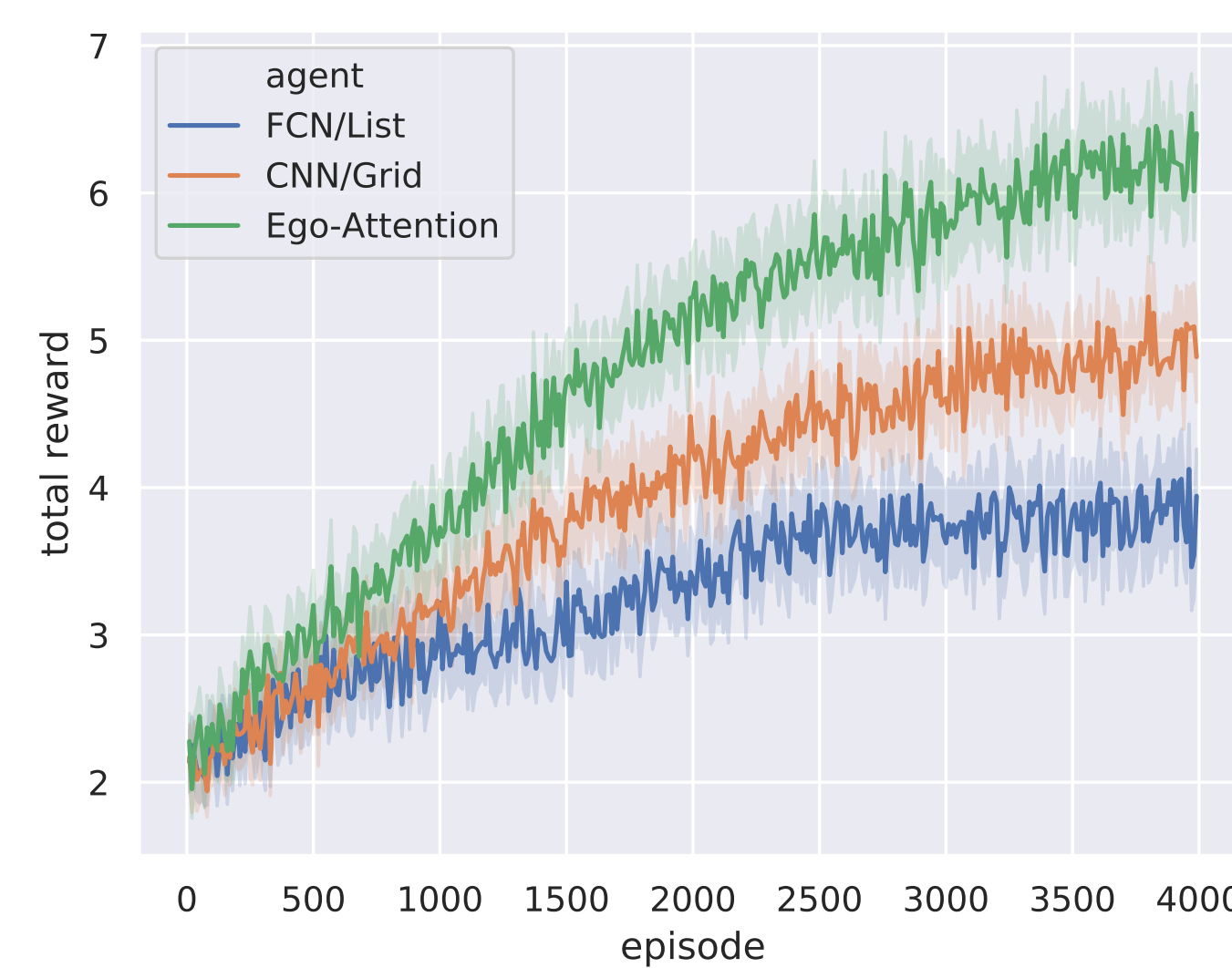
Ego-attention block

Experiments

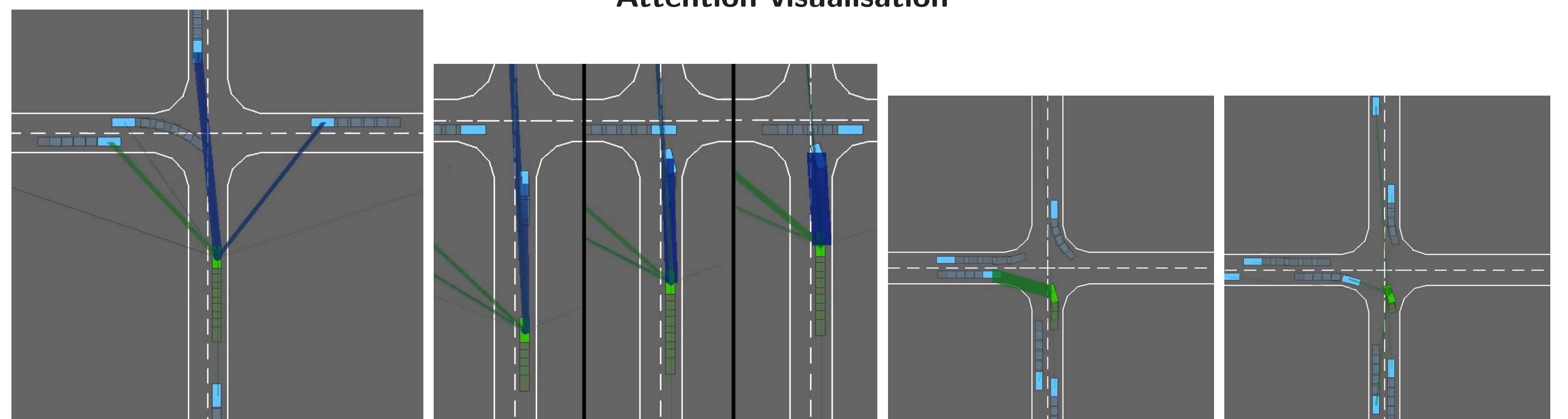
Agents

Agent	FCN/List	CNN/Grid	Ego-Attention
Input sizes	[15, 7]	[32, 32, 7]	[·, 7]
Layers sizes	[128, 128]	Convolutional layers: 3 Kernel Size: 2 Stride: 2 Head: [20]	Encoder: [64, 64] Attention: 2 heads $d_k = 32$ Decoder: [64, 64]
Number of parameters	3.0e4	3.2e4	3.4e4
Variable input size	No	No	Yes
Permutation invariant	No	Yes	Yes

Performances



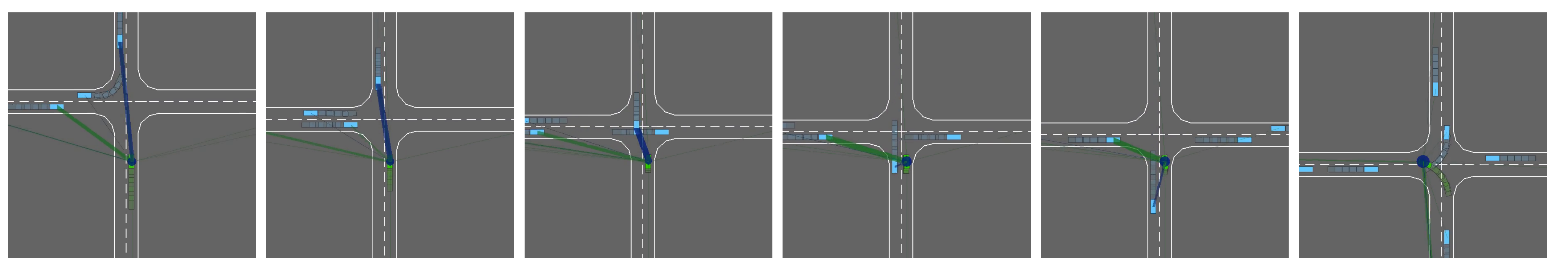
Attention visualisation



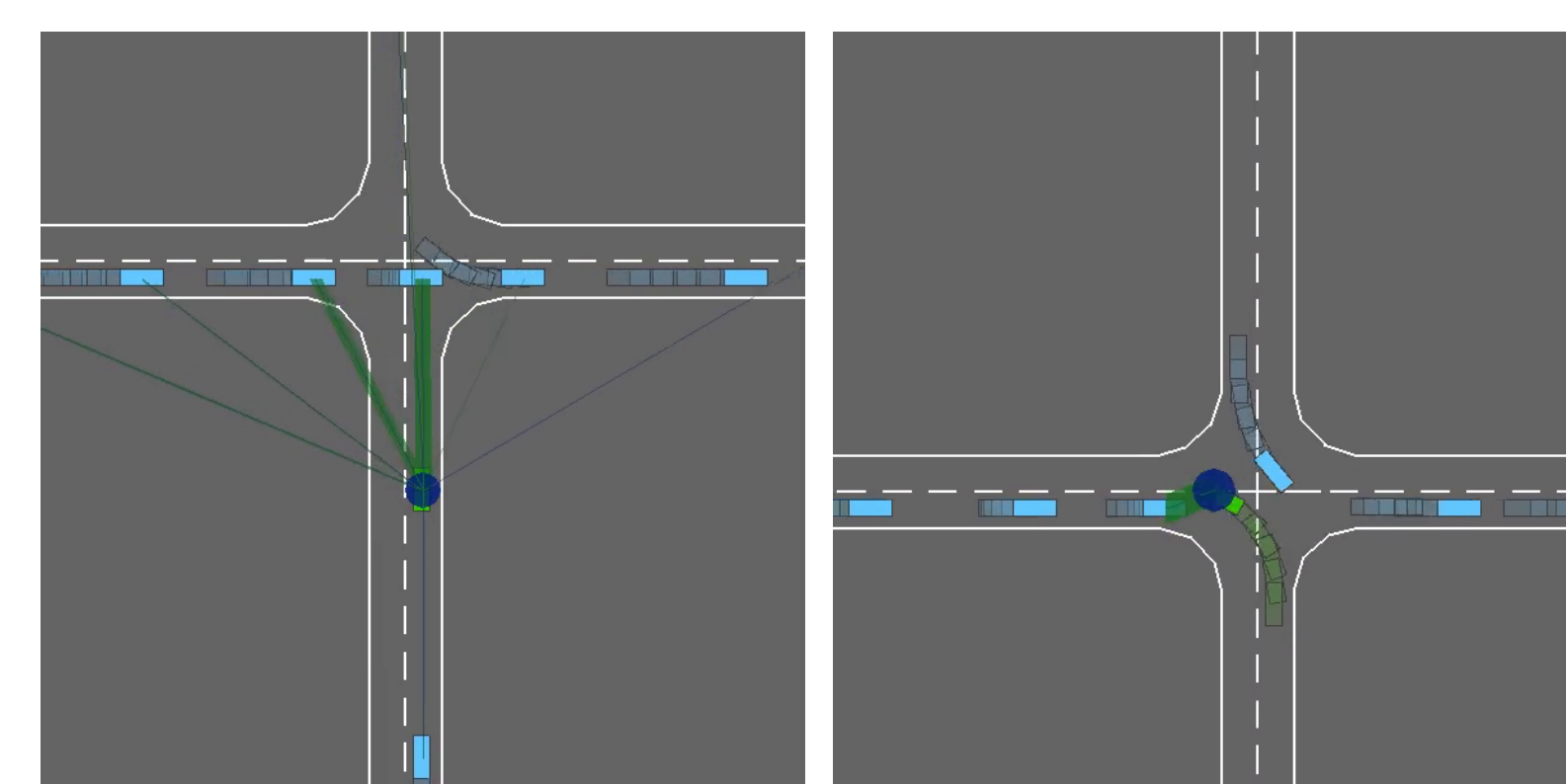
Head specialisation

Distance

Sensitivity to uncertainty



A full episode



Exploiting interaction patterns