



Pedestrians' Understanding of a Fully Autonomous Vehicle's (FAV) Intent to Stop: Utilizing Video-based Crossing Scenarios

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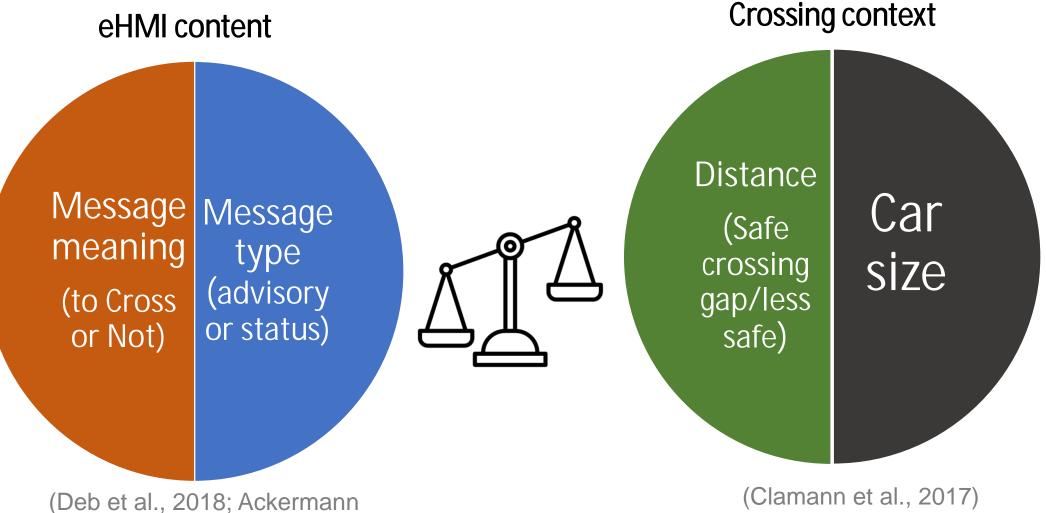
Scientific Background

- External Human Machine Interface (eHMI) improves interaction, initial trust, understanding. (Clamann et al., 2017; Ackermans et al., 2020; Kaleefathullah et al., 2020; Deb, et al. 2018)
- Pedestrians tend to look at the eHMI before making the crossing decision, however they do not necessarily comply. (Hochman et al., 2020)
- Pedestrians' decisions to cross depend on the eHMI suggestion and crossing conditions, e.g., vehicles' distance from the crossing place. (Mahadevan, Somanath, & Sharlin 2018; Tabone et al., 2021)



Motivation

What affects pedestrians understanding and behavior?



et al., 2019)

The Goal

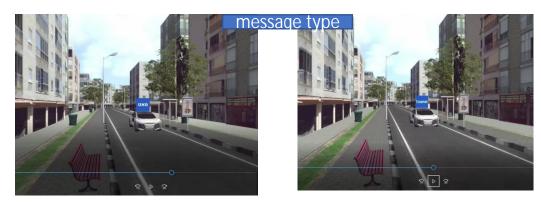
Examine the influence of factors related to the crossing context (distance, car size) and to the eHMI content (message meaning, message type), on pedestrian understanding & behavior in dynamic situations.

Method – Dynamic situations - Video based scenarios

In-Person Experiments

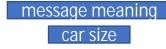














Method – The intermediate questionnaire

Did you understand the FAV message? (yes/no)

How confident are you in your decision? (On 10-point rating scale)

To what extent did you experience the situation as dangerous?

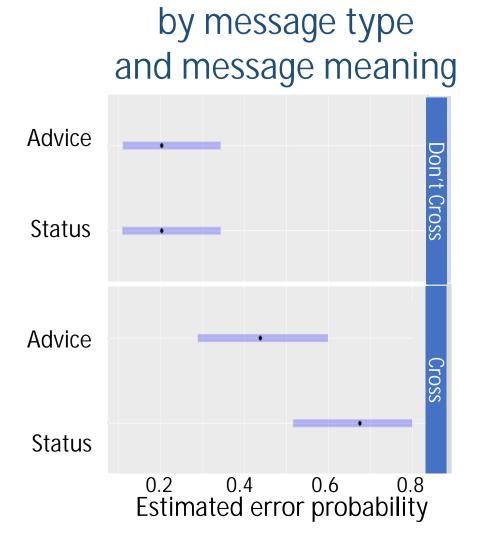
What was the FAV's intention? (short free text answer)

Measuring Understanding

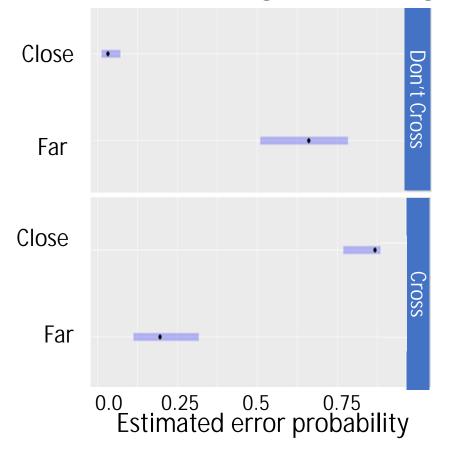
- Error probability- was defined as the incompatibility of the participant's crossing decision (whether to cross or not) with the eHMI recommendations. (Ackermann et al., 2019)
- Response time the time from the moment the video was initiated until the participant pressed a decision button. (Hochman et al., 2020)
- Subjective questionnaires subjective questionnaires. (Deb, Carruth, and Strawderman, 2020; Tabone et al., 2021)
- Eye-tracking measures Total fixations duration, the total number of fixations on the e-HMI, Gaze distribution. (Hochman et al., 2020; Liu et al., 2020)

Results - Error probability

incompatible -47 % , compatible- 53 %

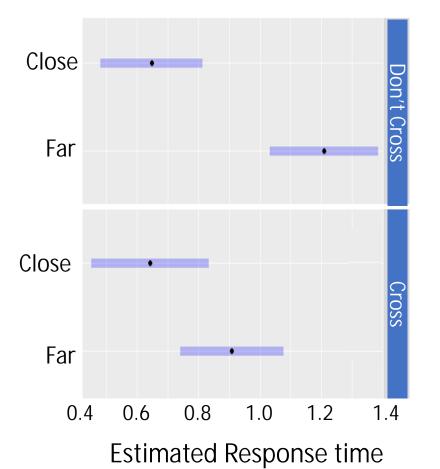


by distance and message meaning



Results – Response time

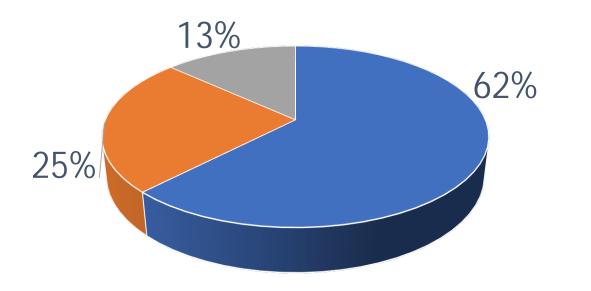
By distance and message meaning



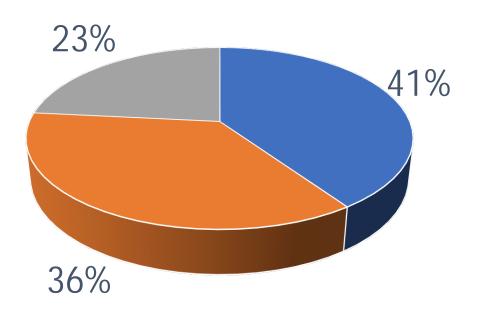
RT was analyzed only for the compatible responses

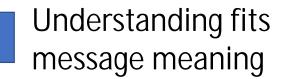
Results - Pedestrian's subjective Understanding





Incompatible responses (47%)





Understanding doesn't fit message meaning

Pedestrian declare They did not understand

Incompatible responses

Incompatible responses when pedestrian understood occurred :

- FAV was Close and the suggestion was to Cross (78%).
- FAV was Far and the suggestion was Not to cross (92%).

When pedestrians did not understand they mainly decided:

- Not to cross in the Close distance when suggested to cross (77%).
- To Cross in the Far distance when suggested not cross (95%).

36 %

Discussion



FAV was Close suggestion was CROSS

FAV was **Far** suggestion was **STOP**

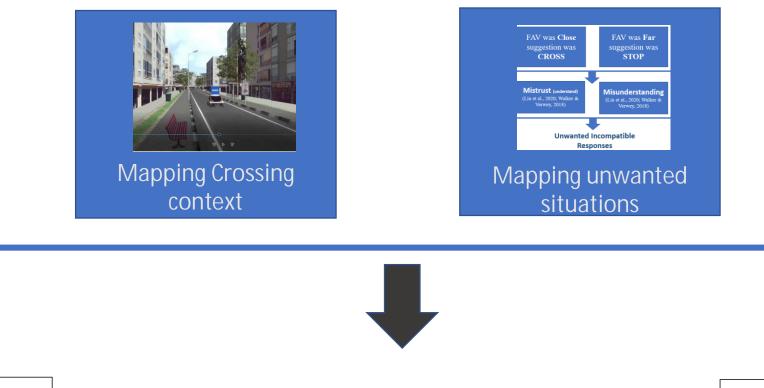


Mistrust (understand) (Liu et al., 2020; Walker & Verwey, 2018)

Misunderstanding (Liu et al., 2020; Walker & Verwey, 2018)

Unwanted Incompatible Responses

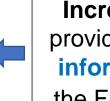
Practical implementation



Increase Understanding through design



Provide e-HMI design that encourage higher compatible decisions and provide fast RT, and minimize number of fixations on the e-HMI



Increase trust by providing pedestrian information about the FAV reliability

Ongoing & Future Work

Ongoing work

- Examine Few FAVs at a certain time.
- Investigate the effect of time pressure.



Future work

- Increase trust by providing pedestrian information about FAV reliability.
- Explore effect of sounds of eHMI on pedestrians estimate the FAV distance, increase awareness of its intentions.
- Examine more complex crossing opportunities (more lanes, two-way streets, various car distances, speeds, etc.).





Questions? THE ISRAELI SMART TRANSPORTATION RESEARCH CENTER



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