〔国際会議発表〕

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発 表 論 文	Motion Planning based on Learning Models of Pedestrian and Driver Behaviors	

概　　要：

　The IEEE conference on Intelligent Transportation Systems（ITS）is one of the best conferences in the field of ITS. The state-of-the-art research and future prospect relating to intelligent transportation systems are presented and discussed in this conference. This conference not only accepts academic paper, but also includes the paper from industry side. It is really good chance to discuss with participants for emerging trends and challenges with practical implications.

　The autonomous driving is one of the most popular research topics in the ITS field. There are intensive discussions about the various aspects of autonomous driving in this conference, such as localization, sensing, and vehicle control. In the future, autonomous vehicles will be allowed to join human-driven vehicles on our road, we have to consider the safety problem from the point view of the hybrid traffic situation. Autonomous vehicles are supposed to react in the same way as human drivers, rather than too cautious and careful as robots. More human-like and natural motion-planning can avoid confusing pedestrians and other drivers, and smooth traffic flow. In order to control the vehicle like human drivers, we proposed to develop the motion planning based on learning models of pedestrian and driver behaviors. The result of our proposal, which is entitled "Motion Planning based on Learning Models of Pedestrian and Driver Behaviors", has been presented in the conference ITSC 2016.