

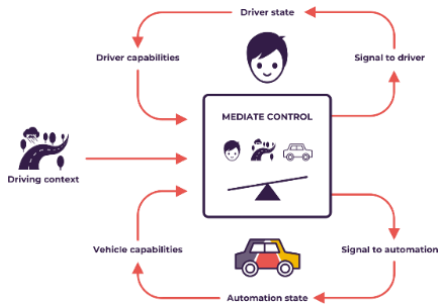
REINFORCEMENT LEARNING FOR SWITCHING CONTROL OF SEMI-AUTOMATED VEHICLES WITH DRIVER FATIGUE

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BACKGROUND

Automated driving technology is growing rapidly

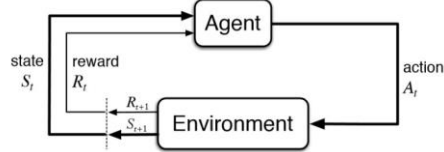
MEDIATOR will develop a safe mediating system for drivers in automated vehicles



Markov Decision Process (MDP): discrete-time stochastic control process to model decision-making problems



Reinforcement Learning (RL): training of machine learning models to make a sequence of decisions



GOAL



Determine the optimal actions to guarantee driving safety and driver comfort in decision logic for specific use case of fatigue

METHOD

- Build an MDP model for the problem
- Use existing RL algorithms to evaluate the performance
- Compare with the baseline policy

MDP FORMULATION

1 - FATIGUE REPRESENTATION

- KSS is used to quantify the sleepiness level
- Alert (KSS = 1~4)
 - Neither alert nor sleepy (KSS = 5)
 - Signs of sleepiness (KSS = 6~7)
 - Sleepy (KSS = 8~9)

2 - ACTIONS

- Do Nothing
 - Correct Fatigue
 - Suggest Shift Automation
 - Shift to Automation
 - Emergency Stop
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EVALUATION

- OpenAI Baselines algorithms: DQN, A2C, TRPO
- 3 different metrics to evaluate
 - Driving **safety**
 - Driving **comfort**
 - Decision **efficiency**

RESULTS

Algorithms	Unsafe Actions (%)	DHFL (s)	Fixed Scenarios (%)
baseline	3.80	1.34	36.53
DQN	3.22	1.29	87.53
A2C	23.06	2.58	16.97
TRPO	3.21	1.30	67.16

Table 1: Driving Safety Metrics

Algorithms	Duration of Being in Fatigue (%)
baseline	2.74
DQN	1.58
A2C	5.89
TRPO	1.49

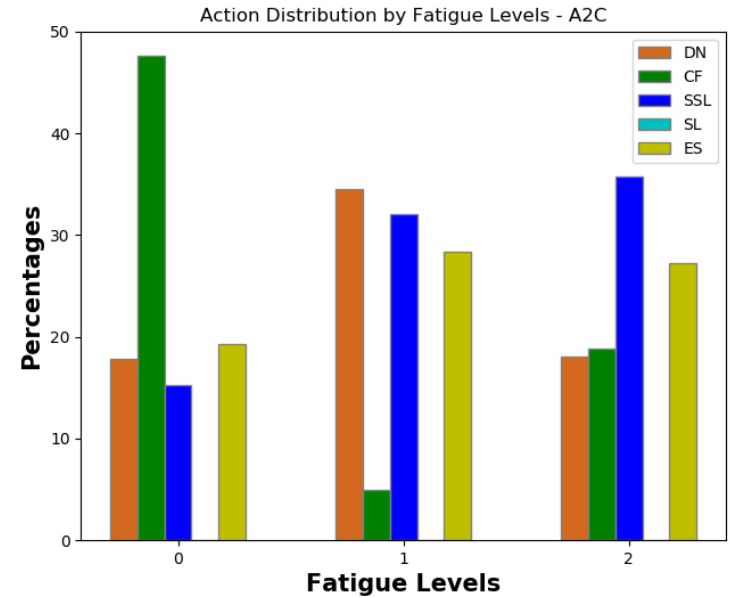
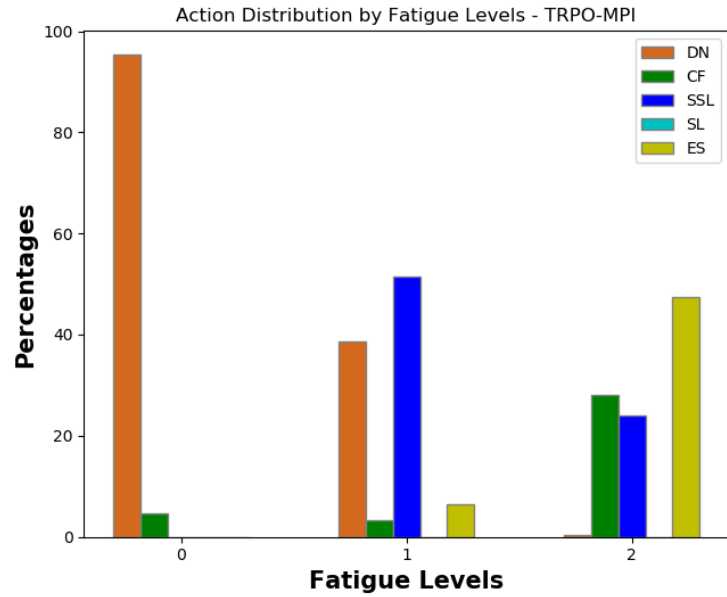
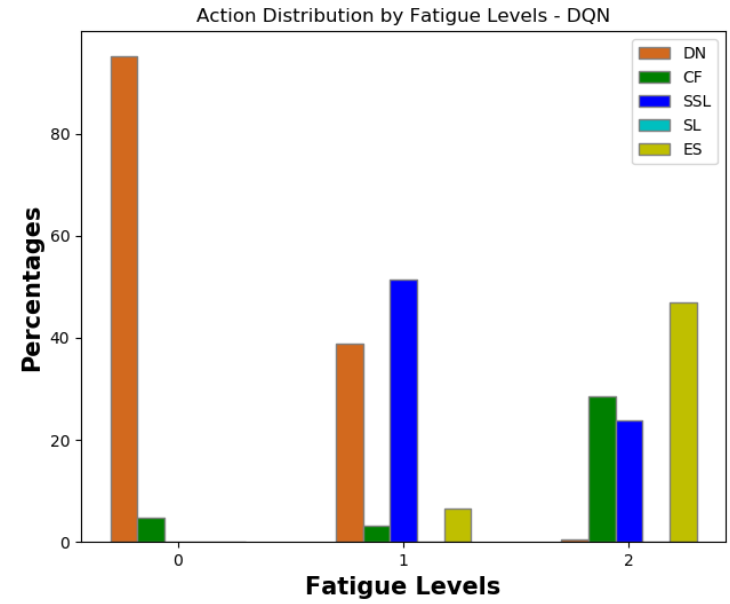
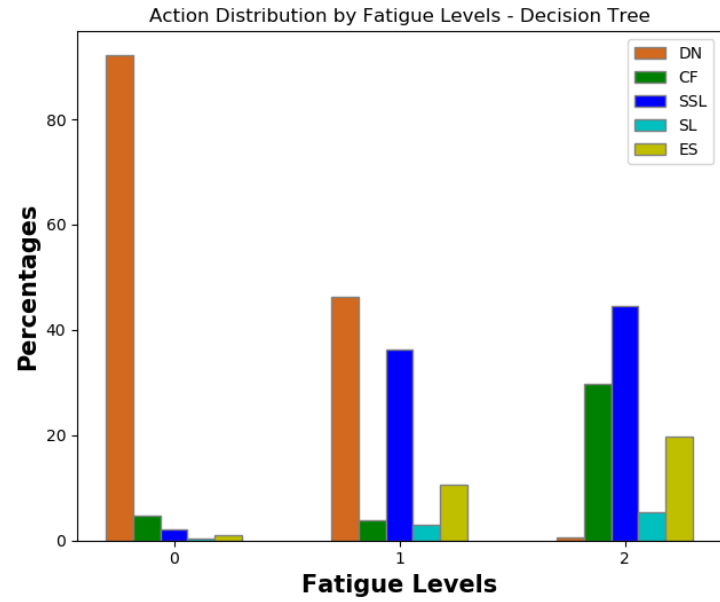
Table 2: Driving Comfort Metrics

Algorithms	Time to Solve Critical Scenario (s)
baseline	2.80
DQN	2.67
A2C	1.63
TRPO	2.64

Table 3: Decision Efficiency Metrics

CONCLUSION

- DQN and TRPO outperforms other algorithms
- A2C is the worst algorithm
- More successful algorithms than baseline policy
- Further improvements by trying more algorithms



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