Cyclists’ predictions of what a car driver will do next at intersections

Kovacsova, Natalia; de Winter, Joost; Hagenzieker, Marjan

Publication date
2017

Document Version
Publisher's PDF, also known as Version of record

Published in

Citation (APA)

Important note
To cite this publication, please use the final published version (if applicable).
Please check the document version above.

Copyright
Other than for strictly personal use, it is not permitted to download, forward or distribute the text or part of it, without the consent of the author(s) and/or copyright holder(s), unless the work is under an open content license such as Creative Commons.

Takedown policy
Please contact us and provide details if you believe this document breaches copyrights.
We will remove access to the work immediately and investigate your claim.
Cyclists’ predictions of what a car driver will do next at intersections

N. Kovácsová*†, J. C. F. de Winter*, M. P. Hagenzieker#†

* Department of Biomechanical Engineering
Delft University of Technology
Mekelweg 2, 2628 CD, Delft, The Netherlands
email: {n.kovacsova, j.c.f.dewinter}@tudelft.nl

# Department of Transport & Planning
Delft University of Technology
Stevinweg 1, 2628 CN, Delft, The Netherlands
email: m.p.hagenzieker@tudelft.nl

† SWOV Institute for Road Safety Research
PO Box 93113, 2509 AC The Hague, The Netherlands

Keywords: predictions, bicycle-car interaction, survey, crowdsourcing.

1 INTRODUCTION

In the Netherlands, 30% of fatal crashes between 2010 and 2015 involved a cyclist [1], with a large portion of these crashes occurring at intersections in urban areas. Contributing factors to driver-cyclist collisions at intersections are not only inadequate visual search, but also incorrect expectations about the other’s intentions [2]. Research also suggests that crashes between drivers and cyclists often happen even when the cyclist must have seen the approaching car [2].

The ability to anticipate future events is crucial for safe performance in traffic [3]. Recently, research has started on hazard anticipation in cycling. For example, an experiment using a hazard perception test has found that adult cyclists detect hazards earlier than children [4]. Furthermore, results from an eye-tracking experiment using animated video clips showed that cyclists are more likely to look at an approaching car (e.g., a car on a collision course) than to a car that has stopped before the intersection or a car that has passed the intersection [5]. However, it is unknown at which point in time and based on which visual cues a cyclist can predict that a perceived hazard becomes an actual hazard (i.e., that the car driver will not yield to a cyclist).

We developed a video-based survey with the aim to gain an understanding of cyclists’ predictions in hazardous intersection situations. The following research questions were addressed herein:

1. How do cyclists’ predictions of the behavior of a car change in the moments prior to a crash or near miss with that car?
2. Is there a difference in cyclists’ predictions of the car’s behavior between crash and near miss scenarios?

2 METHODS

2.1 Participants

A total of 1,344 participants from 65 countries were recruited through the crowdsourcing service CrowdFlower. 739 individuals (471 males, 267 females, and 1 unknown) who met eligibility and quality control criteria (i.e., older than 18 years, correct answers to the quality control items), and who indicated that they cycle at least 1–3 times per week in the summertime were included in the study. Data were collected between February 27 and March 7, 2017. The participants’ mean age was 34.27 (SD = 10.63), ranging between 18 and 70 years.

2.2 Materials and procedure

Traffic video clips from a cyclist’s point of view were collected from publically available YouTube postings. We selected intersection scenarios in which a car was crossing the cyclist’s path and in which a hazardous car was visible for at least 2 s prior to this crossing. A total of nine hazardous and one nonhazardous scenarios were extracted from YouTube. The hazardous scenarios included an approaching car that was not giving right of way to the cyclist, resulting in a crash (five scenarios) or a near miss because the cyclist reacted promptly (four...
scenarios). The nonhazardous scenario was an approaching car that stopped in front of the bicycle path. The nonhazardous scenario was included with the aim to assess whether participants could discriminate between hazardous and non-hazardous scenarios. In addition, one extra nonhazardous scenario was extracted from YouTube and used as a practice clip to familiarize participants with the task.

All downloaded clips were stored at a frame rate of 29.97 fps. Using a video editing method proposed by [6], each clip started with a frozen frame containing a 3 s countdown in the right bottom of the screen, after which the clip was played. To examine how cyclists’ predictions change over time prior to when a car crosses the cyclists’ path, five freeze conditions of each clip were created using Adobe Premier Pro CC 2017. First, a very late freezing moment was created by removing 5 frames (= 0.17 s) from the moment the car either entered the bike path or the moment the car stopped in the nonhazardous scenario. From this point of each clip, eight additional frames were removed four times to create four additional versions of each clip: late (= 0.43 s), intermediate (= 0.70 s), early (= 0.97 s), very early (= 1.24 s) freezing moments (see Fig. 1). Thus, the very late freezing moment was temporally closest to the conflict (hazardous scenarios) or the car’s stopping (nonhazardous scenario). The time between the very late freezing moment and the crash varied between clips from 0.23 to 0.70 s. After the video had played, the last frame was frozen. From the moment of the freeze, a ‘relevant’ hazardous car was encircled in the clips for 2 s, after which the same static image remained visible for another 2 s. The 10 clips with the very late freezing moments were between 13.75 and 21.42 s long (including the 7 s of frozen frames). In total, 50 experimental clips (10 intersection scenarios * 5 freeze conditions) were created. These 50 clips were divided into 5 different sets, and a participant was randomly allocated to 1 of 5 sets by CrowdFlower. Accordingly, each participant saw each of the 10 intersection scenarios only once and encountered each of the five freeze conditions twice during the survey. The order of the freeze conditions and the order of the intersection scenarios were counterbalanced across participants.

After each clip, participants were asked to indicate their responses to eight items: (1) perceived risk (indicated on a 7–point Likert scale), (2) potential cyclist’s (own) behavior, (3) prediction of the driver’s behavior, (4) certainty about the driver’s behavior (7–point Likert scale), (5) factors that contributed to the prediction of the driver’s behavior (multiple options), (6) priority rules, (7) number of times the video was replayed, (8) color of the encircled car (this was a quality control item). Items 2 and 3 had two response options based on game theory [7]: Yes, I would slow down vs. No, I would continue cycling at this speed and Yes, the car driver will slow down and let the cyclist cross first vs. No, respectively. It took on average 20 min to complete the survey.

### 3 RESULTS

Preliminary results of responses to Items 2 and 3 (Fig. 2) show that the percentage of participants who predicted that the car driver will not let the cyclist cross first (left panel) and that they themselves would slow down (right panel) increased over time in the hazardous scenarios (blue and black lines) and decreased over time in the nonhazardous control scenario (green line). Participants’ predictions in the near miss scenarios appear to show earlier information pick-up about drivers not letting the cyclist cross first compared to the crash scenarios (left panel). Similarly, participants reported that they would slow down earlier in near miss scenarios compared to crash scenarios (right panel).

---

This work is licensed under the Creative Commons Attribution 4.0 Unported License. To view a copy of this license, visit [http://creativecommons.org/licenses/by/4.0/](http://creativecommons.org/licenses/by/4.0/)
CONCLUSIONS

Our results suggest that cyclists’ predictions of what a car driver will do in intersection scenarios develop over time, with the responses for the very late freezing moment (i.e., the videos where the freeze was temporally closest to the conflict) being the most accurate. Further, differences in accuracy of predicting driver behavior were observed between near miss and crash scenarios, which might be attributed to different visual cues present in the clips. In order to investigate which factors (e.g., speed/path of the car, line/markers on the road, traffic rules) contributed to cyclists’ predictions and self-reported behavior, a follow-up analysis is planned. In addition, in the final paper we will report the results for the remaining survey items.

ACKNOWLEDGEMENTS

This work has been supported by the People Programme (Marie Curie Actions) of the European Union’s Seventh Framework Programme FP7/2007-2013/under REA grant agreement n° 608092.

REFERENCES