Streetscore - Predicting the Perceived Safety of One Million Streetscapes

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Abstract

Social science literature has shown a strong connection between the visual appearance of a city’s neighborhoods and the behavior and health of its citizens. Yet, this research is limited by the lack of methods that can be used to quantify the appearance of streetscapes across cities or at high enough spatial resolutions. In this paper, we describe ‘Streetscore’, a scene understanding algorithm that predicts the perceived safety of a streetscape, using training data from an online survey with contributions from more than 7000 participants. We first study the predictive power of commonly used image features using support vector regression, finding that Geometric Texton and Color Histograms along with GIST are the best performers when it comes to predict the perceived safety of a streetscape. Using Streetscore, we create high resolution maps of perceived safety for 21 cities in the Northeast and Midwest of the United States at a resolution of 200 images/square mile, scoring ~1 million images from Google Streetview. These datasets should be useful for urban planners, economists and social scientists looking to explain the social and economic consequences of urban perception.

1. Introduction

How does the appearance of a neighborhood impact the health and behavior of the individuals that inhabit them? During the last decades numerous research efforts have explored this question. This research has shown an association between neighborhood disorder and criminal behavior through the well-known ‘broken windows theory’ [26, 11], but also an association between neighborhood disorder and health outcomes, such as the spread of STDs [2], the incidence of obesity [6], and rates of female alcoholism [12].

Until recently, most data on the physical appearance of urban environments was based on low throughput surveys [15, 19]. More recently, however, online data collections methods where humans evaluate images, using experts [7] or crowdsourcing [22], have increased the availability of urban perception data, but not to the extent needed to create global maps. In fact, even the most ambitious crowdsourcing efforts [22] have a limited throughput, being able only to rank images from a handful of cities at a resolution of less than 10 images per square mile. These constraints limit the possibility of using survey based methods to create global maps of urban perception.

The good news about crowdsourced studies is that they provide an ideal training dataset for machine learning methods building on scene understanding literature in computer vision. A trained algorithm, in turn, can be used to create high resolution maps of urban perception at required spatial and geographical scales.

Here, we demonstrate that a predictor trained using generic image features and the scores of perceived safety from a crowdsourced study can accurately predict the safety scores of streetscapes not used in the training dataset. We evaluate the predictive power of different image features commonly used for scene understanding and show that this predictor can be used to extend existing datasets to images and cities for which no evaluative data is available.

2. Image Ranking using Trueskill

We use publicly available data from the crowdsourced study by Salesses et al [22] to train our algorithm. In this study, participants in an online game were shown two Google Streetview images randomly chosen from the cities of New York, Boston, Linz and Salzburg (fig. 1-(a)). Participants were asked to choose one of the two images in response to the question: ‘Which place looks safer?’. 7,872 unique participants from 91 countries ranked 4,109 images using 208,738 pairwise comparisons (or ‘clicks’).

We convert these preferences to a ranked score for each image using the Microsoft Trueskill algorithm [8]. Trueskill uses a Bayesian graphical model to rate players competing in online games. In our case, we consider each image to be the winner of a two-player contest when it is selected in response to a question over another image. Each player’s skill is modeled as a $N(\mu, \sigma^2)$ random variable, which gets updated after every contest. The update equations for a two-
3. Training a Computational Model

One would be inclined to believe that people’s perception of safety is highly subjective. However, Salesses et al. [22] demonstrate that the results obtained from their study are not driven by biases in age, gender or location of the participants, but by differences in the visual attributes of images. Hence creating a computational model for perceived safety based only on image features is feasible.

We draw upon previous work on image aesthetics whose goal is to predict the perceived beauty of photographs. Early research [4, 16] in this area was based on features extracted using rules from photography theory and psychology. Recently, however, task-independent generic image features have been found to be more effective for this purpose [18]. Similarly, we choose generic image features (e.g. [27, 14]) over rule-based features because it is not possible to create an exhaustive list of features for a set of images that is open and unknown.

Next, we describe our feature extraction process.

3.1. Image Feature Extraction

Figure 1-(c) shows eight images from our training dataset sorted from low to high scores. The typical high scoring image contains suburban houses with manicured lawns and streets lined with trees; while the typical low scoring image contains empty streets, fences, and industrial buildings. To predict their perceived safety, the image features need to capture this variance in appearance. Following Xiao et al. [27], we extract multiple generic image features which were shown to perform well for semantic scene classification, as summarized in Table 1. Specifically we extract GIST, Geometric Classification Map, Textron Histograms, Geometric Texton Histograms, Color Histograms, Geometric Color Histograms, HOG2x2, Dense SIFT, LBP, Sparse SIFT histograms, and SSIM.

Once we compute image features we train a predictor for the perceived safety of images (qs) using Support Vector Regression as explained below.

3.2. Prediction using Support Vector Regression

To predict an image’s perceived safety, we choose ν-Support Vector Regression (ν-SVR) [23]. Given input feature vectors x and their corresponding labels y, the goal of Support Vector Regression (SVR) with a linear kernel is to obtain a regression function \( f(x) \) that approximates y, such that,

\[
\begin{align*}
    f(x) &= (w \cdot x) + b, \\
    w, x &\in \mathbb{R}^N, b \in \mathbb{R}
\end{align*}
\]
Table 1. Computation procedure for image features used to predict perceived safety.

<table>
<thead>
<tr>
<th>Feature</th>
<th>Computation Procedure</th>
</tr>
</thead>
<tbody>
<tr>
<td>GIST [21]</td>
<td>Filterbank outputs (8 orientations at 5 different scales) are averaged on a 5 × 5 grid.</td>
</tr>
<tr>
<td>HOG2x2 [3]</td>
<td>124-dimensional 2x2 HOG descriptors are quantized into 300 visual words. Three-level spatial pyramid histograms are constructed and compared using histogram intersection.</td>
</tr>
<tr>
<td>Dense SIFT [13]</td>
<td>SIFT descriptors are extracted in a flat window at two scales on a regular grid at steps of 5 pixels. The descriptors, stacked together for each HSV color channel, are quantized into 300 visual words. Spatial pyramid histograms are used for kernels.</td>
</tr>
<tr>
<td>Sparse SIFT [25]</td>
<td>SIFT features at Hessian-affine interest points are clustered into dictionaries of 1,000 visual words. Two histograms of soft-assigned SIFT features are computed.</td>
</tr>
<tr>
<td>SSIM [24]</td>
<td>Correlation map of a 5 × 5 patch in a 40 pixel window is quantized into 3 radial and 10 angular bins. Spatial histograms constructed from 300 visual words of descriptors.</td>
</tr>
<tr>
<td>Texton Histograms</td>
<td>A 512-dimension histogram is built from a textonmap [17] of each image obtained from a universal texton dictionary.</td>
</tr>
<tr>
<td>Color Histograms</td>
<td>A joint 4 × 4 × 14 histogram of color in CIELab color space for each image.</td>
</tr>
<tr>
<td>Geometric Classification Map</td>
<td>Histograms of geometric class probabilities [9] for ground, vertical, porous and sky.</td>
</tr>
<tr>
<td>Geometric Texton Histograms</td>
<td>Texton Histograms for each geometric class weighed by class probabilities.</td>
</tr>
<tr>
<td>Geometric Color Histograms</td>
<td>Color histograms for each geometric class weighed by class probabilities.</td>
</tr>
</tbody>
</table>

\[
\frac{1}{2}\|w\|^2 + C\sum_{i=1}^{K}|y_i - f(x_i)|_{\varepsilon}
\]

where the value of \(\varepsilon\)—chosen a priori—determines the desired accuracy of approximation.

The key idea of \(\nu\)-SVR [23] is that by choosing \(\nu\) instead of committing to a specific value of \(\varepsilon\) we guarantee that the number of predictions with an error more than \(\varepsilon\) is smaller than \(\nu\). This is achieved by solving the following constrained minimization problem –

\[
\text{minimize} \quad \frac{1}{2}\|w\|^2 + C \cdot \left(\nu + \frac{1}{K} \sum_{i=1}^{K} (\xi_i + \bar{\xi}_i)\right)
\]

subject to \(\langle w \cdot x_i \rangle + b - y_i \leq \varepsilon + \xi_i\)

\(y_i - \langle w \cdot x_i \rangle - b \leq \varepsilon + \bar{\xi}_i\)

\(\xi_i, \bar{\xi}_i \geq 0, \varepsilon > 0\) \hspace{1cm} (3)

3.3. Performance Evaluation

We now evaluate the performance of these features by training an SVR for each feature. We use the Coefficient of Determination (\(R^2\)) between true scores \(q_i\) and predicted scores \(\hat{q}_i\) to evaluate the accuracy of a regression model. \(R^2\) is a quantitative measure for the proportion of total variance of true data explained by the prediction model. It is defined as

\[
R^2 = 1 - \frac{\sum_i (q_i - \hat{q}_i)^2}{\sum_i (q_i - \bar{q})^2}
\]

where \(\bar{q} = \frac{1}{|q|} \sum_i q_i\) \hspace{1cm} (5)

We train the SVR using libsvm [1] and choose the linear kernel with following parameters: \(C = 0.01\), and \(\nu = 0.5\). We determine the optimal \(C\) and \(\nu\) using a grid search to minimize the \(R^2\) of prediction over 5-fold cross-validation.

The performance of individual features for Q-score prediction is summarized in Fig. 2-(a). Geometric Texton Histograms perform the best \((R^2 = 0.4826)\), followed by GIST \((R^2 = 0.4339)\). It is important to note that HOG2x2 and Dense SIFT, which are the top performing features for generic scene classification [27], do not perform as well, with \(R^2 = 0.3841\) and \(R^2 = 0.4283\) respectively. A combination of all features gives \(R^2 = 0.5676\).

**Feature Selection**: Our goal is to develop a trained predictor that can generate a very high resolution dataset of people’s perception of urban environments. To reduce the computational cost of feature extraction from new images, we sought to choose the best three features using feature selection. We use ‘forward selection’ for this purpose. In this method, starting with an empty set, we iteratively add one feature at a time, which increases \(R^2\) the most, over 5-fold cross-validation. This process gives us Geometric Texton Histograms, GIST and Geometric Color Histograms, in that order, as our three best features, with a combined \(R^2 = 0.5365\) (Fig. 2-(b)). It is interesting to note that Geometric Color Histograms provide the most performance improvement after Geometric Texton Histograms and GIST, even though the individual performance of Geometric Color
Histograms is not impressive ($R^2 = 0.3103$). This shows that colors are an important dimension in predicting perceived safety as they provide information that is different from the one contained in textons and GIST.

We refer to a predictor trained using Geometric Texton Histograms, GIST and Geometric Color Histograms as the ‘Streetscore’ predictor and analyze its performance for binary classification as additional performance evaluation.

**Binary Classification**: For binary classification we use ‘low’ ($t_l$) and ‘high’ ($t_h$) thresholds to label images in our test set as ‘unsafe’ or ‘safe’ according to their Q-scores. We study classification accuracy as a function of $\delta = t_h - t_l$, where $t_l = q_s - \sigma q_s / 2$ and $t_h = q_s + \sigma q_s / 2$ and $q_s$ is the average $q_s$ of the test set (Fig. 2-(c)). For $\delta = 0$ (i.e. $t_l = t_h = q_s$) the accuracy of our classifier is 78.42%, whereas for $\delta = 2 \cdot \sigma q_s$ the accuracy is as high as 93.49%, over a 5-fold cross-validation. We note that the accuracy of a random predictor would be 50%.

The robust performance of Streetscore in both classification and regression on this challenging dataset demonstrates that the computed features have good explanatory power for prediction of perceived safety. In the next section, we analyze the performance of Streetscore in different geographical regions of the United States.

4. Perception Maps

To use Streetscore for creating global maps of urban perception, we need to determine the generalization performance of the predictor in terms of geographical distance, that is, determine the spatial range for which we expect the predictions to hold. Are images from New York and Boston good enough to predict the perceived safety of images from all over the world? Or is the predictor trained using these images applicable only in a limited geographical region around New York and Boston? Intuitively, the external validity of the predictor would depend on the similarity between architectural styles and urban planning of the cities being evaluated. There are, however, no quantitative studies on measuring similarities along these axes. Therefore, we use the average median income of a city as a naïve metric to validate the accuracy of Streetscore for cities not in the original crowdsourced study.

First, we use StreetScore to create perception maps for 27 cities across the United States using images densely sampled from Google Streetview at 200 images/square mile (Fig. 3-(a)), scoring more than 1 million images. Then, using 9 cities which lie inside a 200 mile radius of New York City, we compute a linear fit ($L_{qi}$) between the mean Q-score ($q_i$) of a city and its average median family income ($I_c$) according to the 2010 census (Fig. 3-(b)). We find a strong correlation between the two variables (Pearson Correlation Coefficient = 0.81).

This linear regression helps us determine some loose bounds on the geographical region over which the algorithm can be applied given the current training set. Figure 3-(c) shows a plot the residual from $L_{qi}$ of cities as a function of their distance to New York City. This exercise shows that the mean absolute error (MAE) is large for cities in Arizona, California and Texas, indicating that the algorithm does not perform well in these regions. Based on this regression we propose a tentative bound of 1100 miles for the validity of our trained predictor. Certainly we do not expect this radius of validity to be the same in different parts of the world, where architectural gradients might be different. Nevertheless, even if these ranges vary by as much as a factor of two, they would indicate that an algorithm trained with a few images from a given area can be used to map a significant area of its surroundings, which is useful to know for future crowdsourced studies.

Figure 5 shows perception maps for six cities created using Streetscore. Our goal is to create such maps for every city in the Northeast and Midwest of United States and make them available through an interactive website. This dataset should help urban planners, economists and social scientists who are increasingly using data-driven techniques to study the social and economic consequences of urban environments.
5. Discussion and Limitations

Research in visual analysis beyond semantics, such as interestingness [5], beauty [4] and memorability [10], has been a recent topic of interest in computer vision. Our work helps expand this research by focusing on the evaluative dimensions of streetscapes, such as their perceived safety, liveliness and character. As a tool, Streetscore can help urban planners construct better cities. Yet, Streetscore also points to new research directions for the vision community. For instance, a fruitful area of research would involve identifying the objects and features that help explain the evaluative dimensions of a streetscape. Also, by classifying streetscapes evaluatively, it should be possible to advance data-driven rendering techniques that are tuned based on derived evaluative criteria (such as a place that is lively but harmonious).

Our results also show some important limitations. Since it is challenging to encode all the variance of the rich and complex visual world in a limited training dataset, the predictor fails when evaluating images with unusual visual elements not encountered in the training set, such as colorful graffiti, overpasses and modern architecture. (q_s – True Q-score, q_h – Predicted Q-score) crowd, can be used to create ‘perception maps’ of 21 cities from United States at a resolution of 200 images/square mile.

In conclusion, we present a novel computational tool for measuring perceived safety of cities which should inspire more research in quantitative analysis of cities and their impact on its inhabitants. In particular, further research on impact of different visual elements of streetscapes on perception can directly influence the urban planning and architecture community.

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References


Figure 5. Perception maps for 6 cities at 200 images/square mile. An online interactive dataset of perception will be a useful tool for scientists studying social and economic impact of urban environments. (Note: the maps are at different scales)