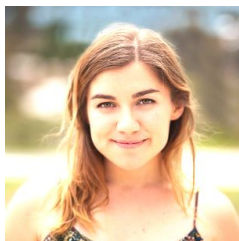


# TRAFFIC CRUISING

DATA SCIENCE FOR SOCIAL GOOD @ UW  
FINAL PRESENTATION | 08.17.17



BRETT BEJCEK  
DSSG FELLOW



ORYSYA STUS  
DSSG FELLOW



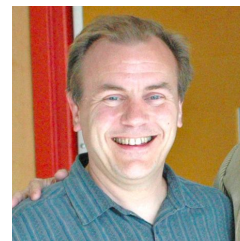
MIKE VLAH  
DSSG FELLOW



ANAMOL PUNDLE  
DSSG FELLOW



VALENTINA STANEVA  
DATA SCIENTIST



VAUGHN IVERSON  
DATA SCIENTIST

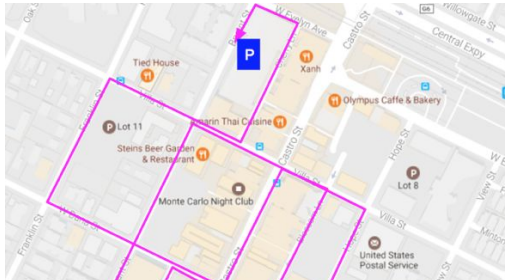


STEVE BARHAM  
PROJECT LEAD

LARGE AMOUNT OF CONGESTION  
CAUSED BY TRAFFIC CRUISING

LOOKING FOR  
PARKING

DEADHEADING  
VEHICLES FOR HIRE



GOOGLE MAPS

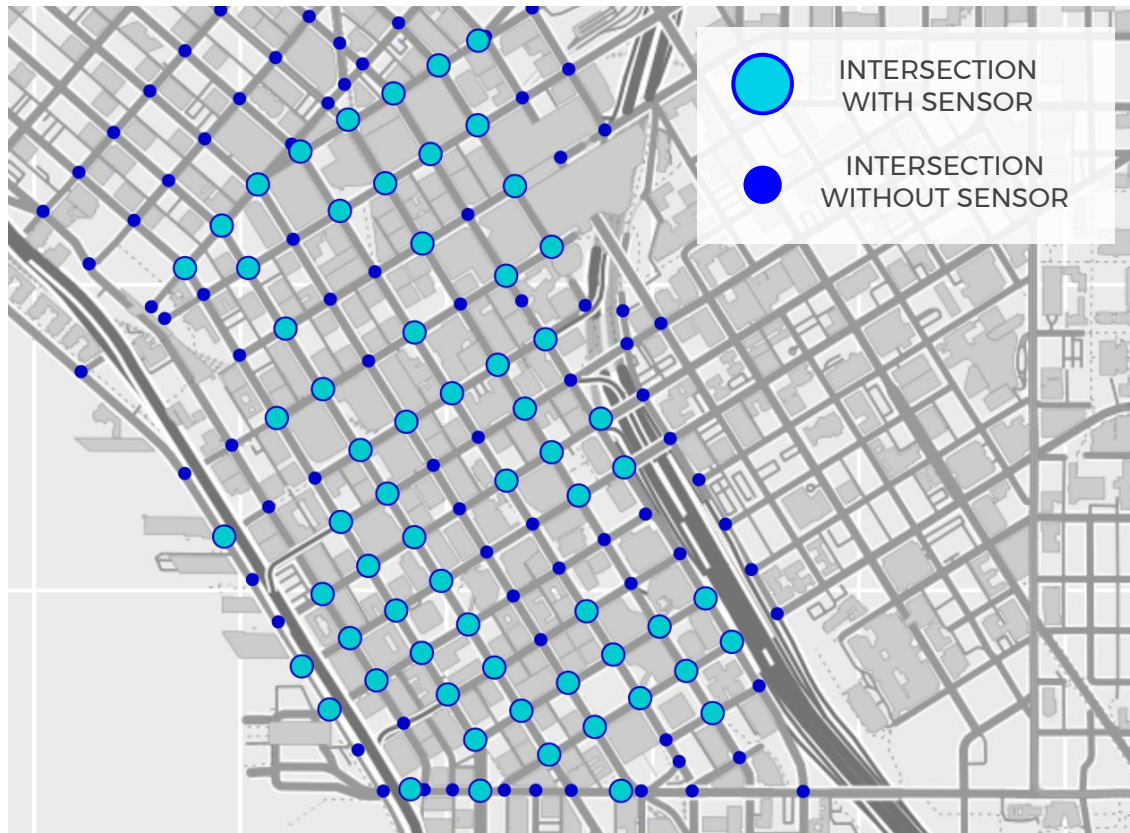


10 MILES      7-13 MILES



SCHALLER CONSULTING

PROBLEM



<u>HASHED MAC</u>	<u>TIME</u>	<u>SENSOR</u>	<u>STRENGTH</u>
KD98SDK8AH	8:32:01	276105	-52
8DJSKDLX0	8:32:01	276102	-55
439WOA09A	8:32:01	265402	-75
777AJDKAL8	8:32:05	293010	-50
QKSJ239A99	8:32:07	251040	-45
DQWPPOA09	8:32:10	265402	-49
KD98SDK8AH	8:32:11	265302	-54

# PROBLEM

# TECHNICAL CHALLENGES

INCOMPLETE GRID

SENSORS ONLY COVER

37%

OF THE GRID.

BIG DATA

SENSORS PRODUCE

200K

OBSERVATIONS / HR.

SENSOR DETECTION

SENSORS DETECT

38%

OF DEVICES W/ WIFI ON.

# PRIVACY AND DATA GOVERNANCE

```
graph TD; A((DATA IS ANONYMIZED)) --- B[INEXACT LOCATION]; A --- C[AGGREGATED VIEWS]; A --- D[RAW DATA NOT RETAINED]; A --- E[DEPLOYABLE BEHIND TRANSPORTATION DATA COLLABORATIVE];
```

INEXACT LOCATION

AGGREGATED VIEWS

DATA IS  
ANONYMIZED

RAW DATA NOT  
RETAINED

DEPLOYABLE BEHIND  
TRANSPORTATION DATA  
COLLABORATIVE

# OBJECTIVES

1

REPURPOSE  
SENSOR  
NETWORK

2

DIFFERENTIATE  
TYPES OF TRAFFIC  
CRUISING

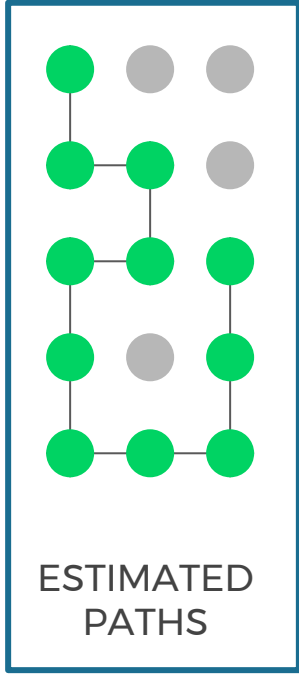
3

VISUALIZE  
WITH A  
HEAT MAP

4

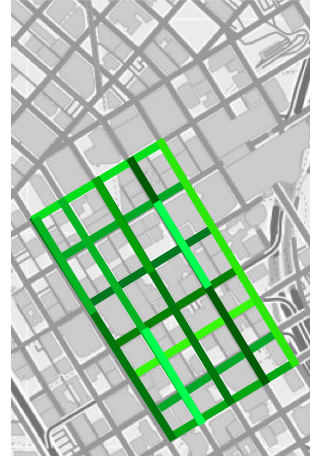
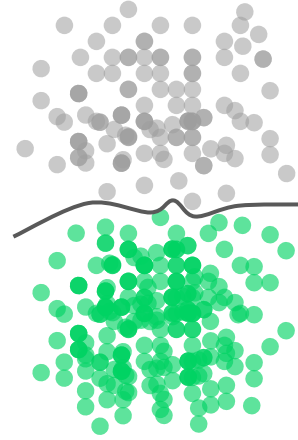
SCALE UP AND  
DEPLOY

ENCRYPTED HASH	TIME	SENSOR
KD98SDK8AHD8X	8:32:00	276105
8DJSKDLSX0WKK	8:32:01	276102
DQWPPOA09DSD	8:32:01	265402
KDOSPALDKSX03	8:32:01	265302
DJKFOSPHSHAH8	8:32:01	265101
0138DSJCVBNAA	8:32:01	273777
ODLPZZZ98A999	8:32:02	265000
NVMCSKDJKLKSS5	8:32:02	265103
QALSJDJKHD0000	8:32:02	265434
DQWPPOA09DSD	8:32:02	273099
0138DSJCVBNAA	8:32:02	273010
ODLPZZZ98A898	8:32:02	265001
ASKDPPPPQLSLAA	8:32:03	265000



25 MPH
2 STOPS
0.35 DISTANCE RATIO
ETC.

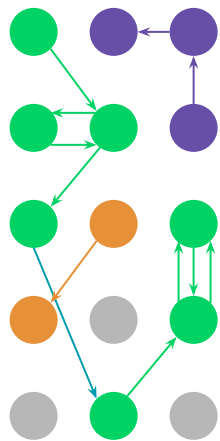
METADATA



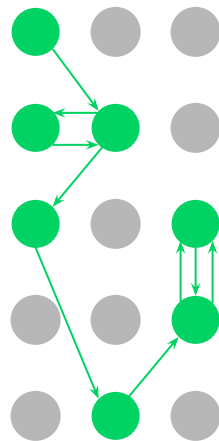
ANONYMOUS  
SENSOR  
READINGS



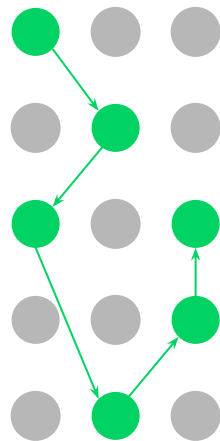
# APPROACH OVERVIEW



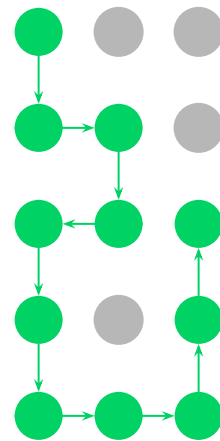
GROUP  
ANONYMOUS  
READINGS



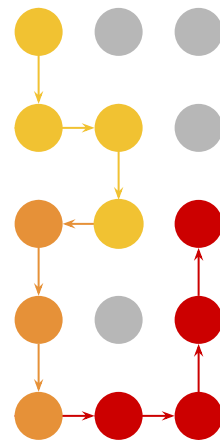
REMOVE SHORT  
PATHS



REMOVE FALSE  
DETECTIONS



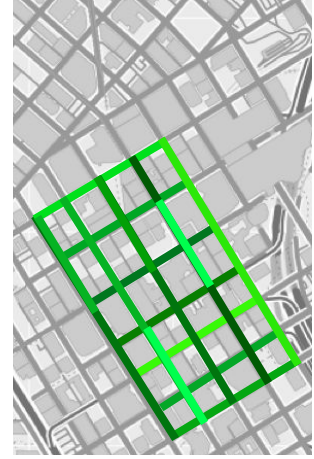
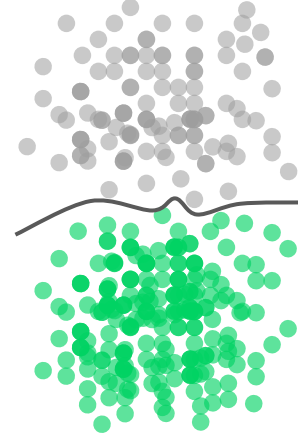
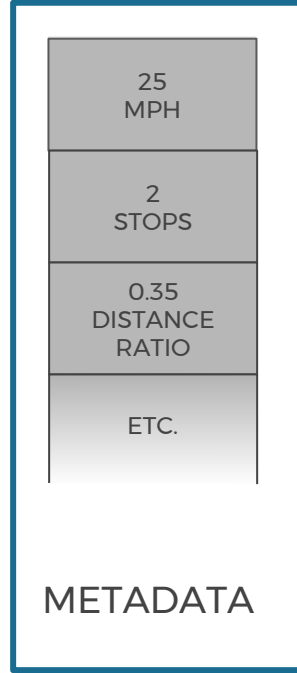
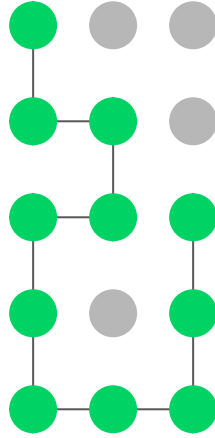
ESTIMATE  
ROUTE



SEGMENT AND  
LABEL

# PIPELINE

ENCRYPTED HASH	TIME	SENSOR
KD98SDK8AHD8X	8:32:00	276105
8DJSKDLX0WKK	8:32:01	276102
DQWPPOA09DSD	8:32:01	265402
KDOSPALDKSX03	8:32:01	265302
DJKFOSPHSHAH8	8:32:01	265101
0138DSJCVBNNA	8:32:01	273777
ODLPZZZ98A999	8:32:02	265000
NVMCSKDJKLKSS	8:32:02	265103
QALSJDJKHD0000	8:32:02	265434
DQWPPOA09DSD	8:32:02	273099
0138DSJCVBNNA	8:32:02	273010
ODLPZZZ98A998	8:32:02	265001
ASKDPPPPQLSLAA	8:32:03	265000



ANONYMOUS  
SENSOR  
READINGS

ESTIMATED  
PATHS

METADATA

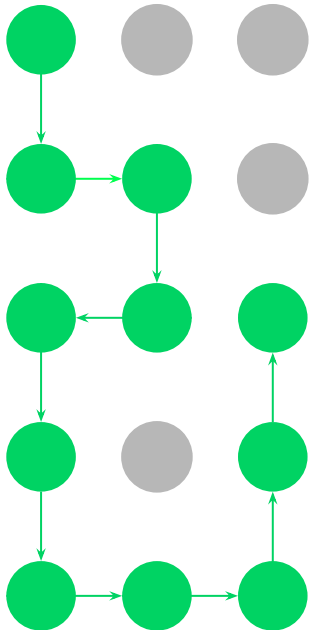
LABELED  
PATHS

AGGREGATE  
HEATMAP

# APPROACH OVERVIEW

# METADATA COLLECTION

## PATH



## FEATURES

NUMBER OF TIMES PATH CROSSED

AVERAGE SPEED

MAX SPEED

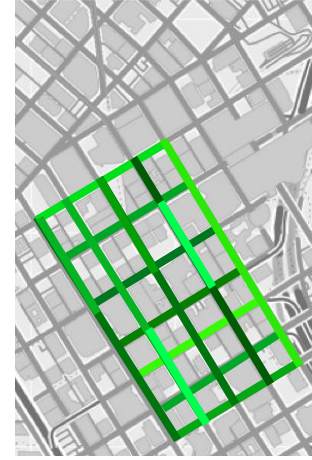
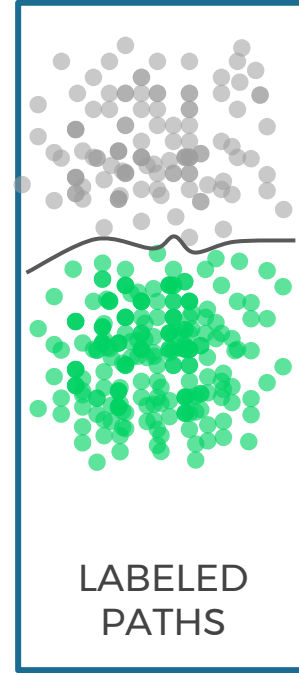
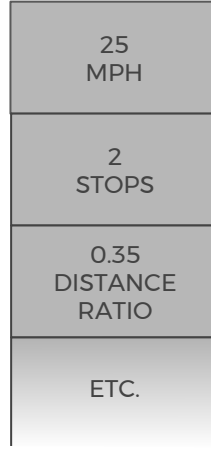
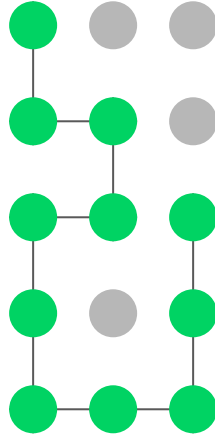
STANDARD DEVIATION OF SPEED

NUMBER OF LONG STOPS

PERCENTAGE OF TIME DRIVING

PERCENTAGE OF TIME WALKING

ENCRYPTED HASH	TIME	SENSOR
KD98SDK8AHD8X	8:32:00	276105
8DJSKDLX0WKK	8:32:01	276102
DQWPPOA09DSD	8:32:01	265402
KDOSPALDKSX03	8:32:01	265302
DJKFOSPHSHAH8	8:32:01	265101
O138DSJCVBNAA	8:32:01	273777
ODLPZZZ98A999	8:32:02	265000
NVMCSKDJKLKSS	8:32:02	265103
QALSJDKJHD0000	8:32:02	265434
DQWPPOA09DSD	8:32:02	273099
O138DSJCVBNAA	8:32:02	273010
ODLPZZZ98A898	8:32:02	265001
ASKDPPPPQLSLAA	8:32:03	265000



ANONYMOUS  
SENSOR  
READINGS



ESTIMATED  
PATHS



METADATA



LABELED  
PATHS



AGGREGATE  
HEATMAP

# APPROACH OVERVIEW

# DEFINING CRUISING

## PROBLEM

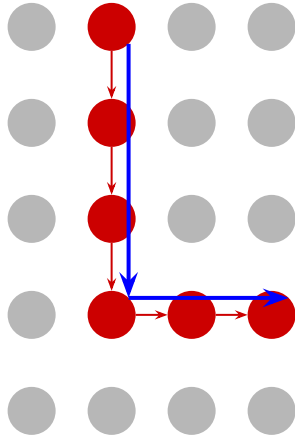
- 1 NO STANDARD DEFINITION OF CRUISING
- 2 CURRENTLY NO GROUND TRUTH

## SOLUTION

- 1 MULTI-STEP CLASSIFICATION
- 2 LABEL SUBSET OF EXTREME CASES
- 3 MACHINE LEARNING TO IDENTIFY CRUISING INDICATORS

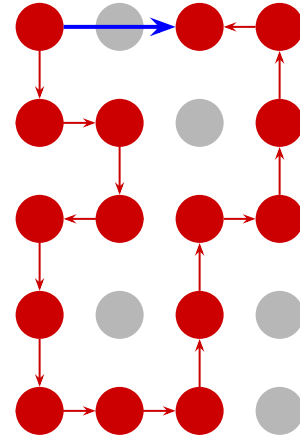
# LABELING

## USING DISTANCE RATIO



$$5 / 5 = 1.0$$

PROBABLY NOT  
CRUISING



$$14 / 2 = 7.0$$

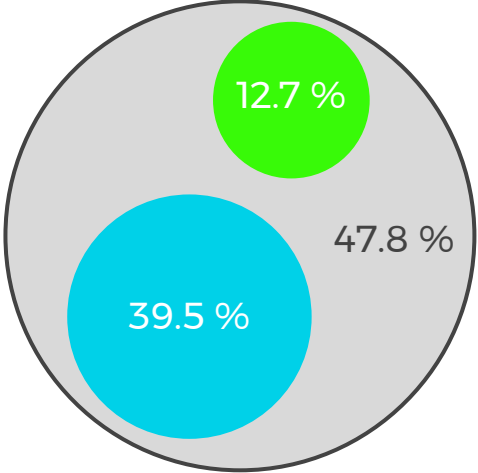
PROBABLY  
CRUISING

# MULTI-STEP CLASSIFICATION



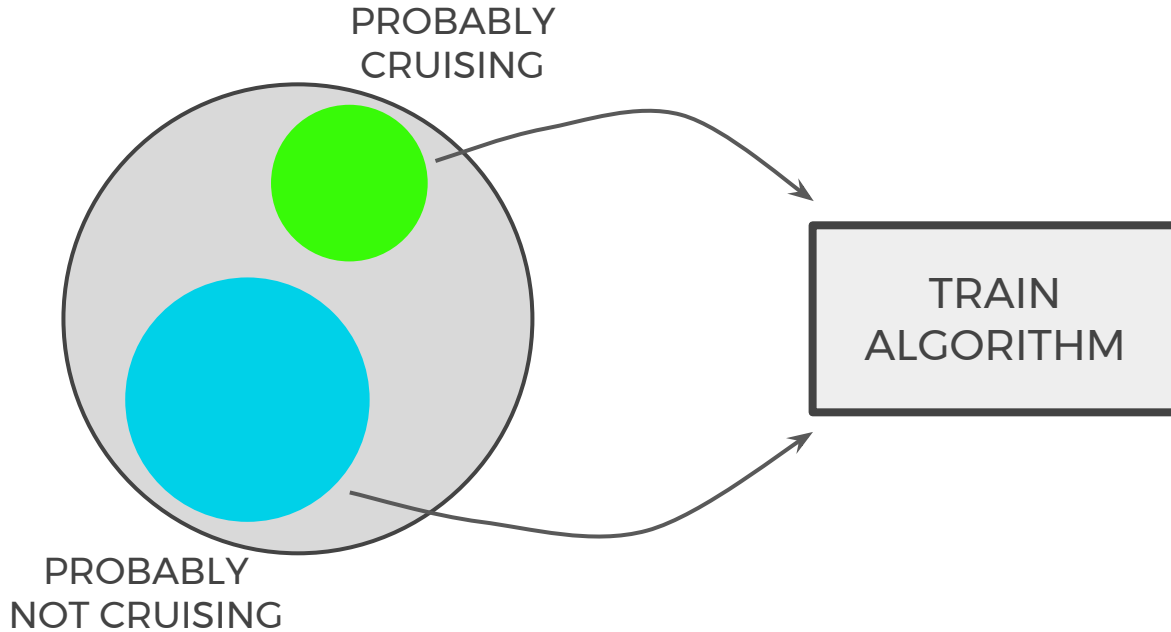
# MULTI-STEP CLASSIFICATION

PROBABLY  
CRUISING

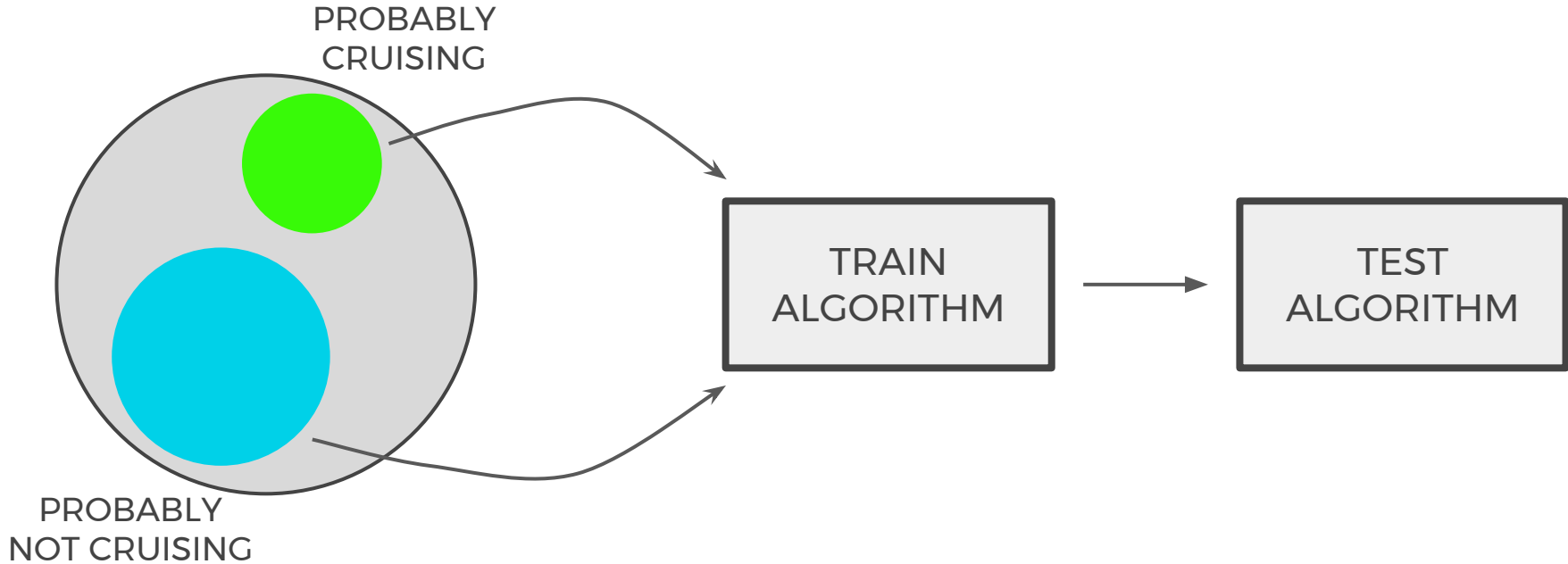


PROBABLY  
NOT CRUISING

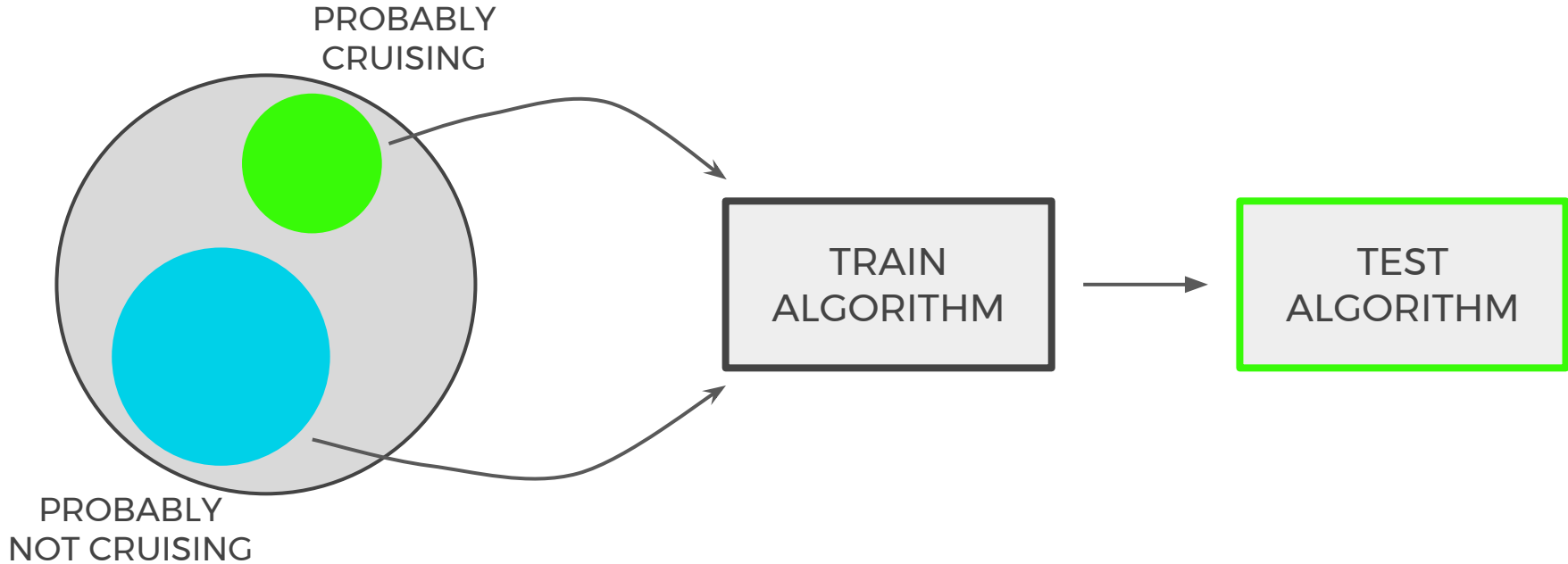
# MULTI-STEP CLASSIFICATION



# MULTI-STEP CLASSIFICATION



# MULTI-STEP CLASSIFICATION



# MULTI-STEP CLASSIFICATION

TESTING ALGORITHM

```
graph TD; A[TESTING ALGORITHM] --> B[DECISION TREE  
ACCURACY: 96.6%]; A --> C[LOGISTIC REGRESSION  
ACCURACY: 91.4%]; A --> D[GRADIENT BOOSTING  
ACCURACY: 97.1%];
```

The diagram illustrates a multi-step classification process. At the top, a box labeled 'TESTING ALGORITHM' is highlighted with a green border. Three arrows point downwards from this box to three separate boxes below. Each box contains the name of an algorithm and its corresponding accuracy percentage: Decision Tree (96.6%), Logistic Regression (91.4%), and Gradient Boosting (97.1%).

DECISION  
TREE

ACCURACY: 96.6%

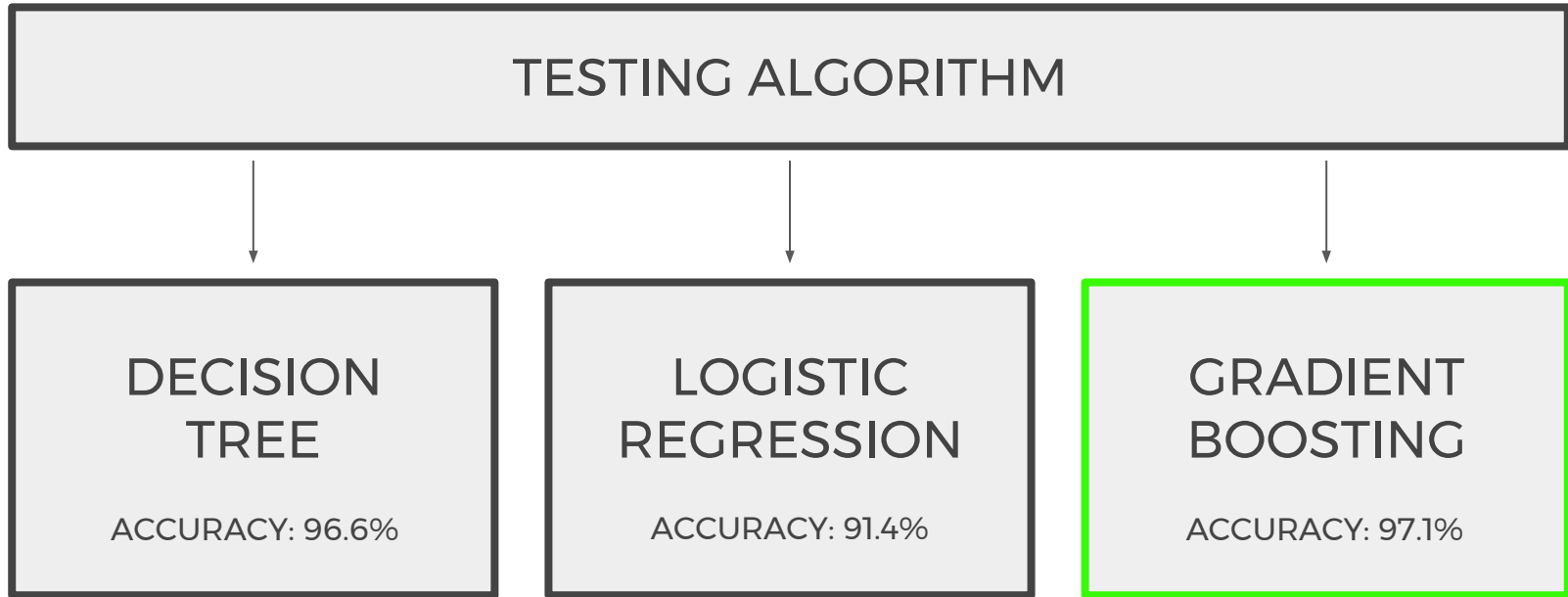
LOGISTIC  
REGRESSION

ACCURACY: 91.4%

GRADIENT  
BOOSTING

ACCURACY: 97.1%

# MULTI-STEP CLASSIFICATION

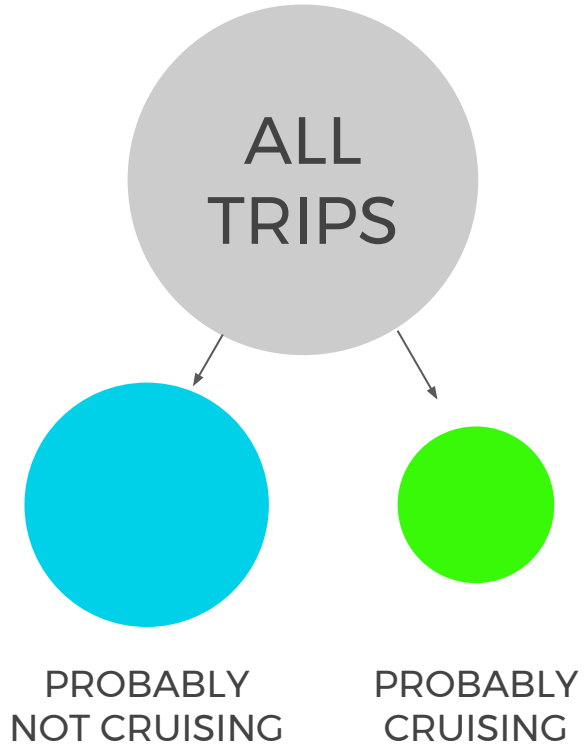


# LABELING ALL DATA

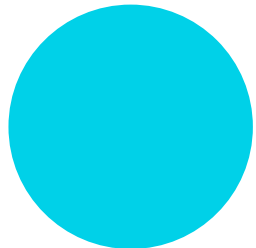
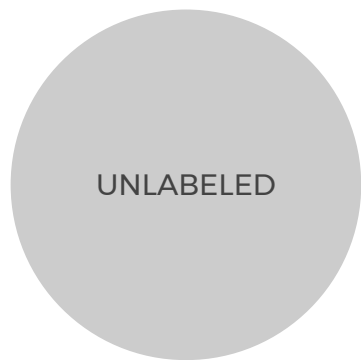


ALL  
TRIPS

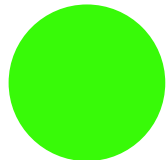
# LABELING ALL DATA



# LABELING ALL DATA

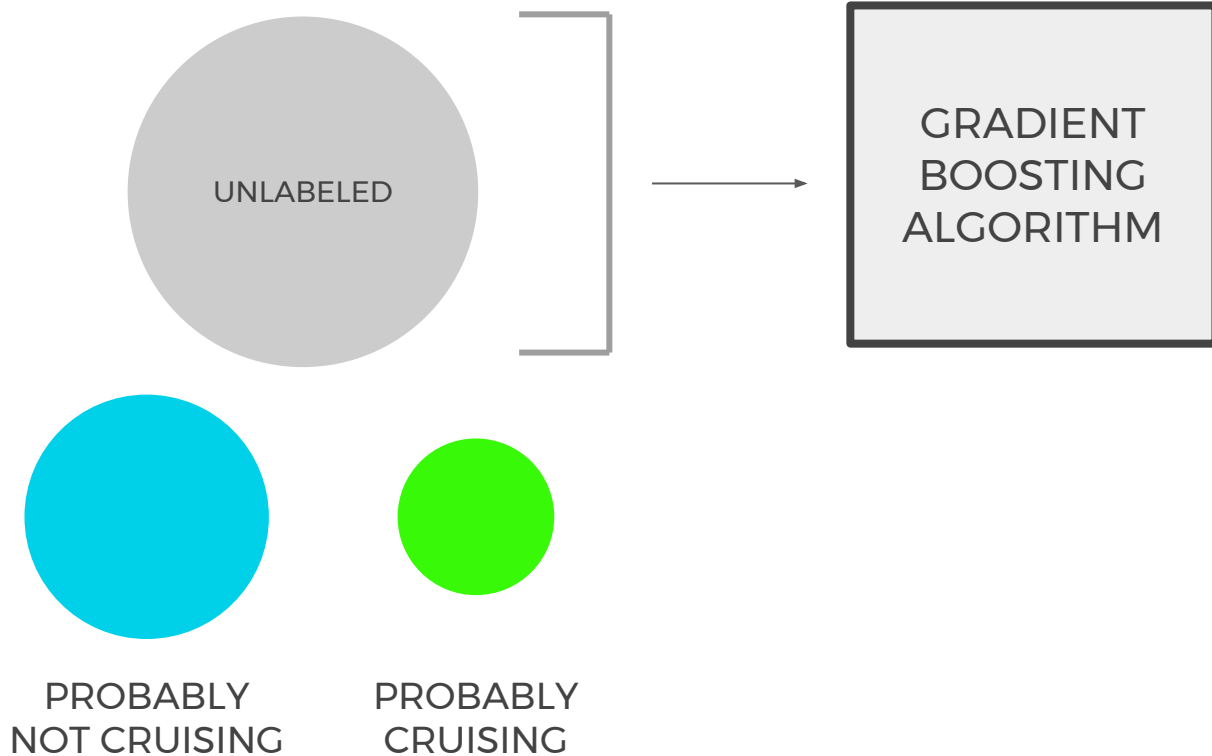


PROBABLY  
NOT CRUISING

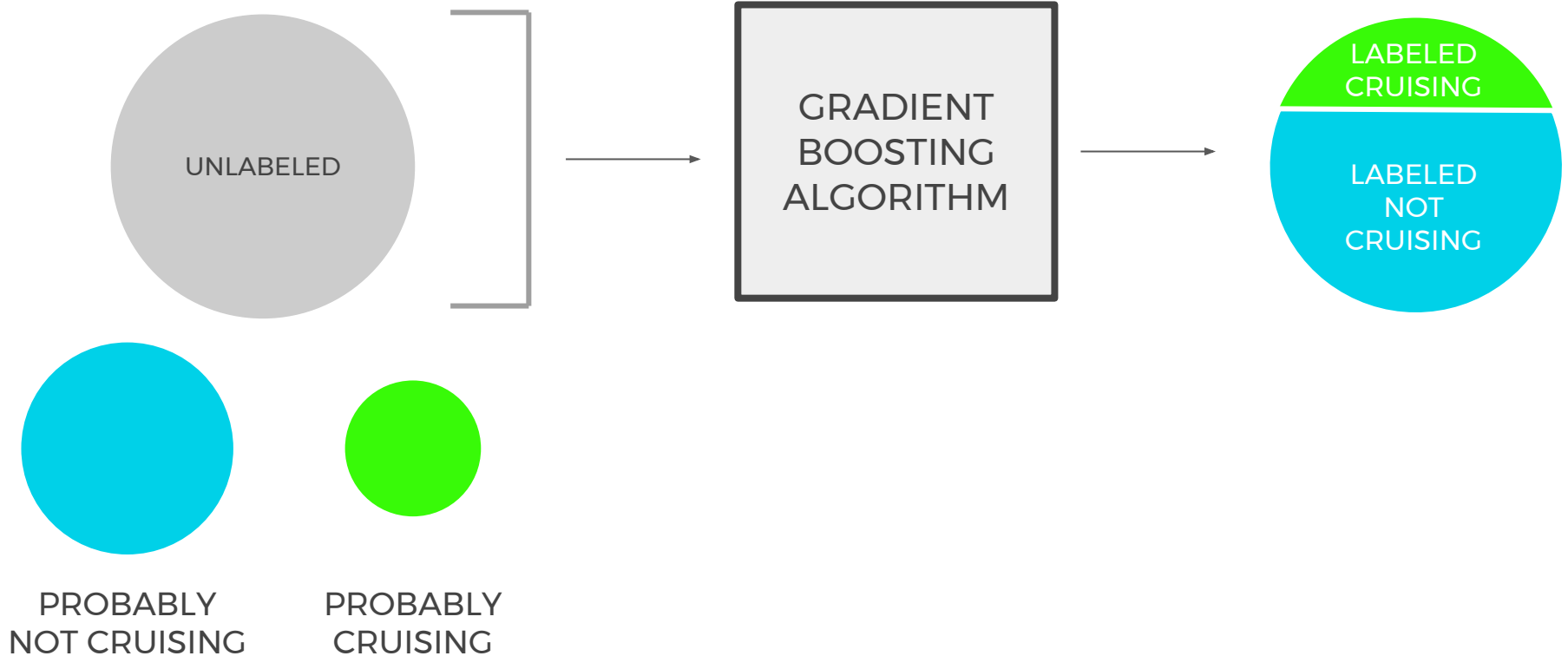


PROBABLY  
CRUISING

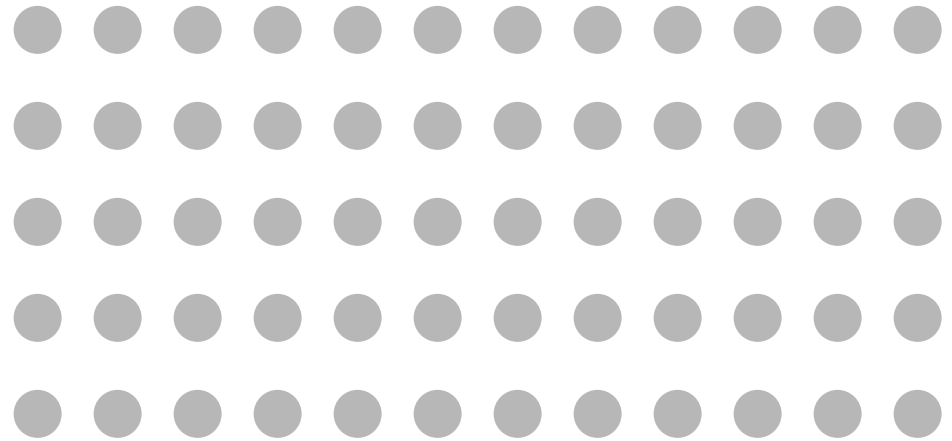
# LABELING ALL DATA



# LABELING ALL DATA



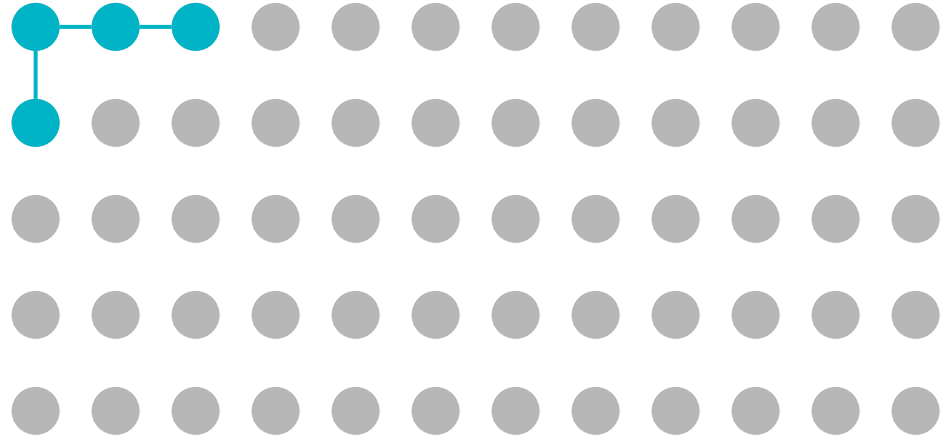
# IDENTIFYING FOR-HIRE VEHICLES



# IDENTIFYING FOR-HIRE VEHICLES

## FOR-HIRE VEHICLE EXAMPLE

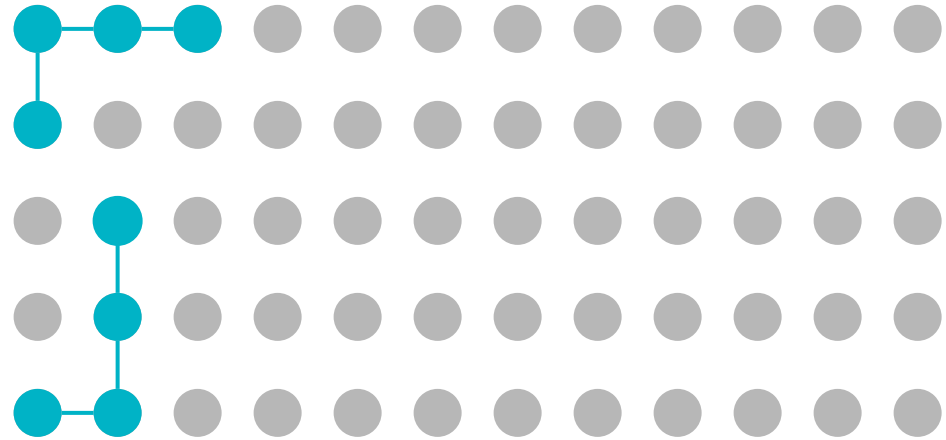
4 LARGE GAPS IN READ TIMES (5 TRIPS)



# IDENTIFYING FOR-HIRE VEHICLES

## FOR-HIRE VEHICLE EXAMPLE

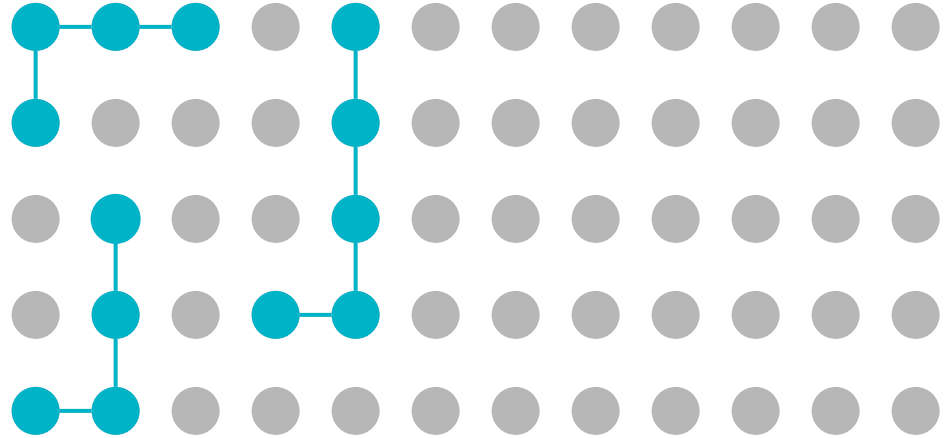
4 LARGE GAPS IN READ TIMES (5 TRIPS)



# IDENTIFYING FOR-HIRE VEHICLES

## FOR-HIRE VEHICLE EXAMPLE

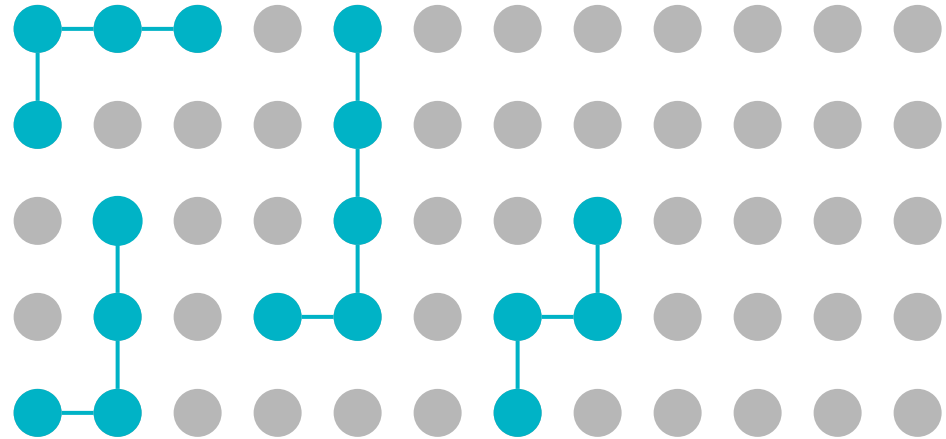
4 LARGE GAPS IN READ TIMES (5 TRIPS)



# IDENTIFYING FOR-HIRE VEHICLES

## FOR-HIRE VEHICLE EXAMPLE

4 LARGE GAPS IN READ TIMES (5 TRIPS)





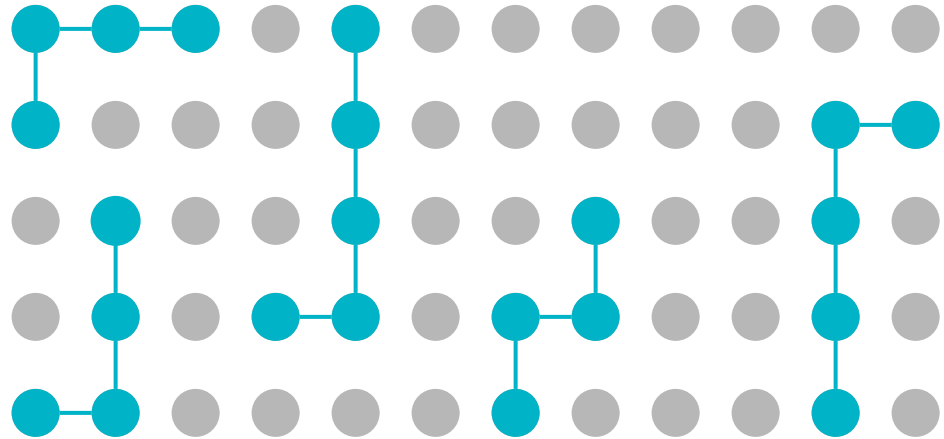
# IDENTIFYING FOR-HIRE VEHICLES

## FOR-HIRE VEHICLE EXAMPLE

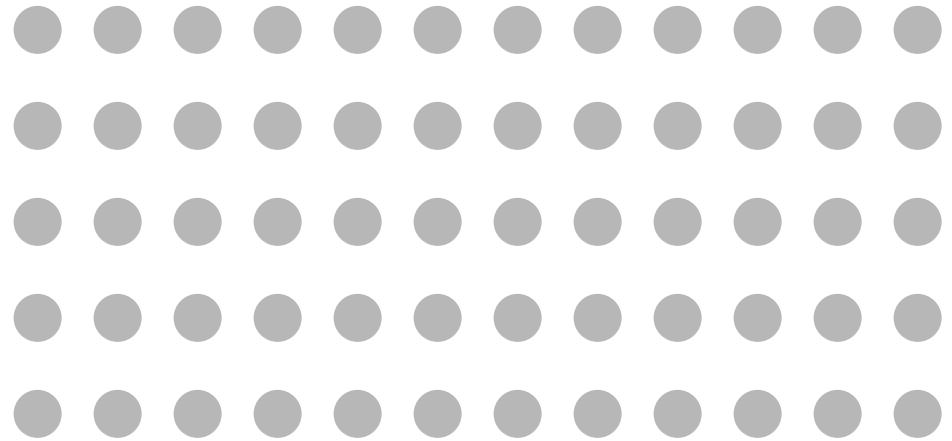
4 LARGE GAPS IN READ TIMES (5 TRIPS)

UNIQUE SENSORS / TOTAL READS =

$22 / 22 = 1.0$  [HIGH DISPERSION]



# IDENTIFYING FOR-HIRE VEHICLES

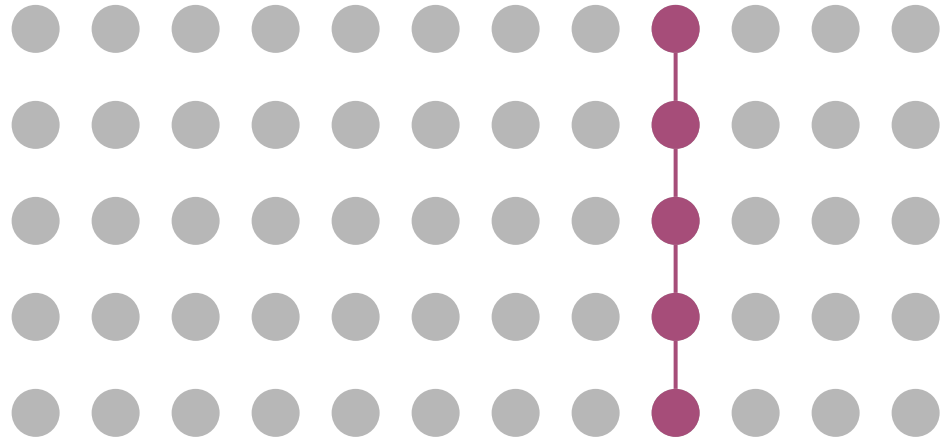


# IDENTIFYING FOR-HIRE VEHICLES

## **BUS** EXAMPLE

---

4 LARGE GAPS IN READ TIMES (5 TRIPS)

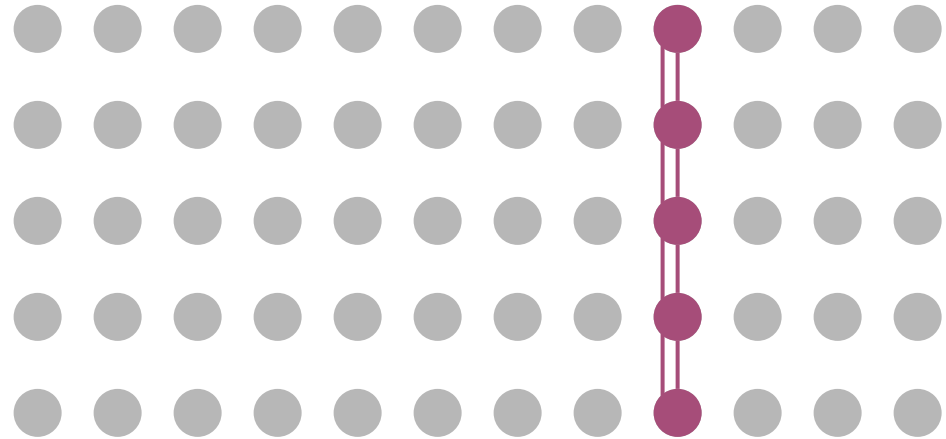


# IDENTIFYING FOR-HIRE VEHICLES

## **BUS** EXAMPLE

---

4 LARGE GAPS IN READ TIMES (5 TRIPS)

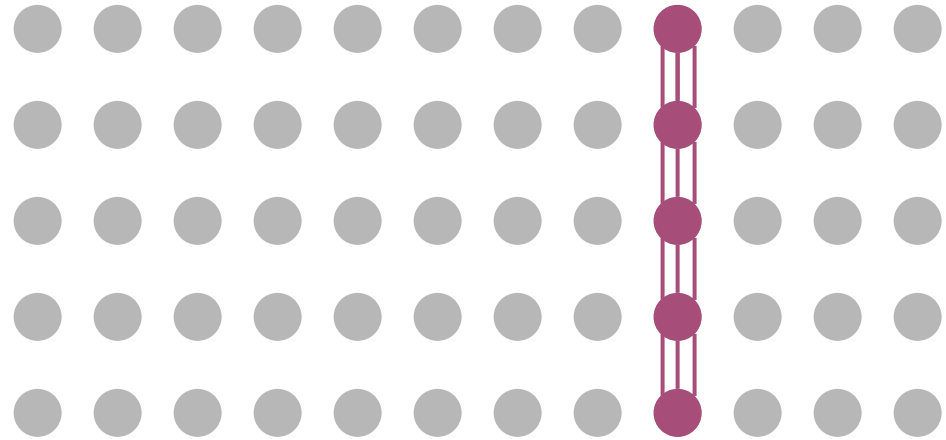


# IDENTIFYING FOR-HIRE VEHICLES

## **BUS** EXAMPLE

---

4 LARGE GAPS IN READ TIMES (5 TRIPS)

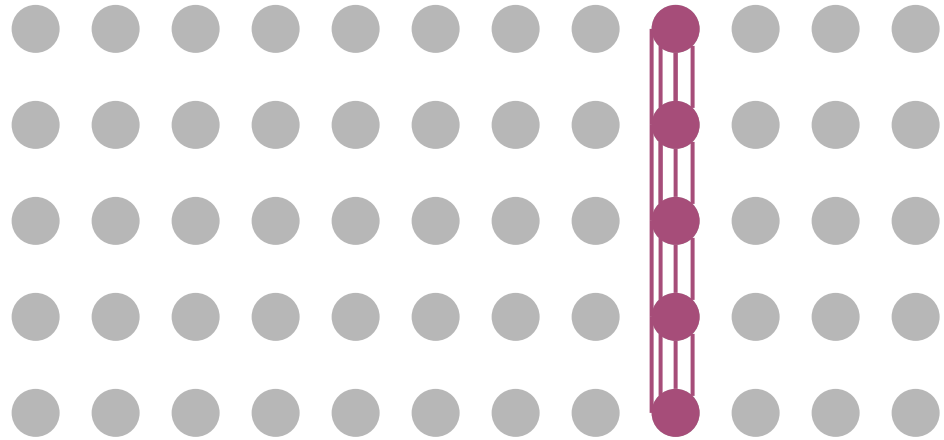


# IDENTIFYING FOR-HIRE VEHICLES

## **BUS** EXAMPLE

---

4 LARGE GAPS IN READ TIMES (5 TRIPS)



# IDENTIFYING FOR-HIRE VEHICLES

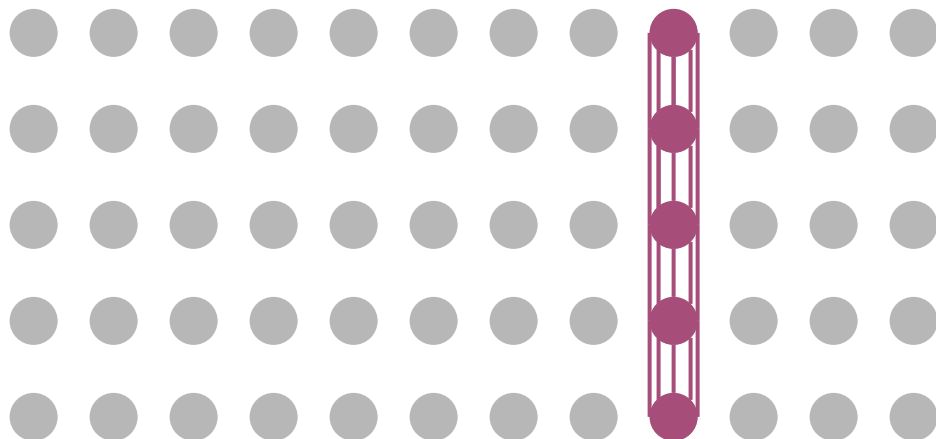
## **BUS** EXAMPLE

---

4 LARGE GAPS IN READ TIMES (5 TRIPS)

UNIQUE SENSORS / TOTAL READS =

$$5 / 25 = 0.2 \quad \text{[LOW DISPERSION]}$$



# IDENTIFYING FOR-HIRE VEHICLES

## **FOR-HIRE VEHICLE** EXAMPLE

4 LARGE GAPS IN READ TIMES (5 TRIPS)

UNIQUE SENSORS / TOTAL READS =

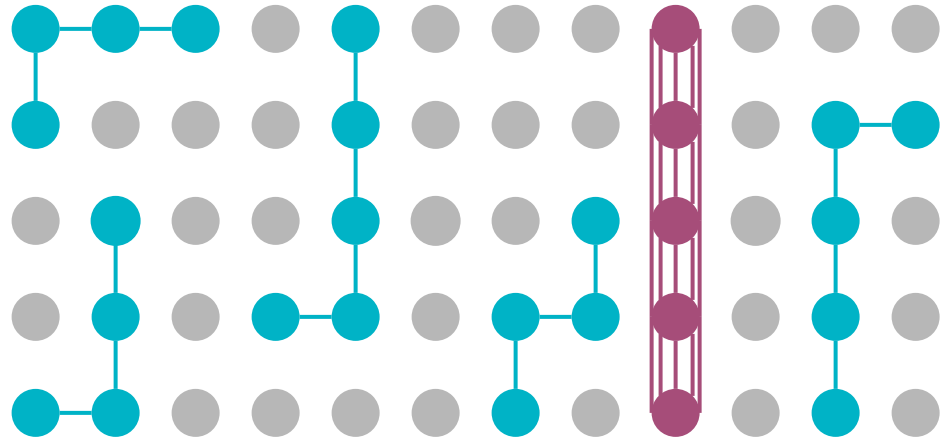
$$22 / 22 = 1.0 \quad \text{[HIGH DISPERSION]}$$

## **BUS** EXAMPLE

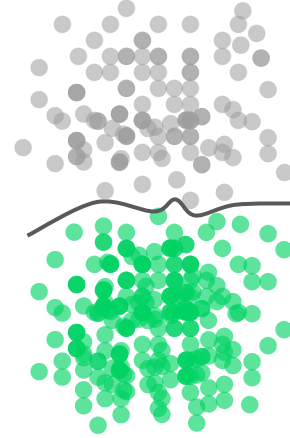
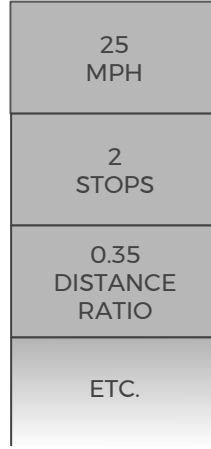
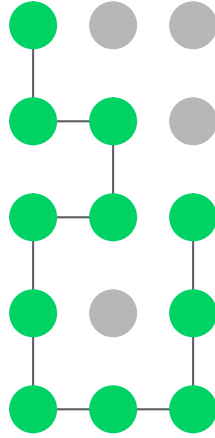
4 LARGE GAPS IN READ TIMES (5 TRIPS)

UNIQUE SENSORS / TOTAL READS =

$$5 / 25 = 0.2 \quad \text{[LOW DISPERSION]}$$



ENCRYPTED HASH	TIME	SENSOR
KD98SDK8AHD8X	8:32:00	276105
8DJSKDLX0WKK	8:32:01	276102
DQWPPOA09DSD	8:32:01	265402
KDOSPALDKSX03	8:32:01	265302
DJKFOSPHSHAH8	8:32:01	265101
0138DSJCVBNAA	8:32:01	273777
ODLPZZZ98A999	8:32:02	265000
NVMCSKDJKLKSSS	8:32:02	265103
QALSJDJKHD0000	8:32:02	265434
DQWPPOA09DSD	8:32:02	273099
0138DSJCVBNAA	8:32:02	273010
ODLPZZZ98A898	8:32:02	265001
ASKDPPPPQLSLAA	8:32:03	265000



ANONYMOUS  
SENSOR  
READINGS



ESTIMATED  
PATHS



METADATA



LABELED  
PATHS



AGGREGATE  
HEATMAP

# APPROACH OVERVIEW



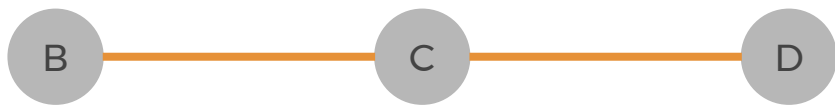
PATH ONE

+



PATH TWO

+



PATH THREE



AGGREGATED COUNTS

# AGGREGATION



# CRUISING IN DOWNTOWN SEATTLE

As part of The Data Science for Social Good Program at The University of Washington, the Traffic Cruising Team has produced a heatmap to identify cruising in the downtown Seattle area.

SELECT TYPE OF CRUISING

**PARKING**

DRUG TRAFFIC / DISORDER

SELECT DAY

**MON**

TUE

WED

THR

FRI

SAT

SUN

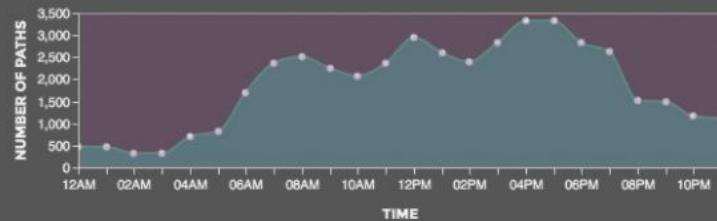
SELECT TIME

**ALL DAY**

MORNING

MIDDAY

EVENING





# CRUISING IN DOWNTOWN SEATTLE

As part of The Data Science for Social Good Program at The University of Washington, the Traffic Cruising Team has produced a heatmap to identify cruising in the downtown Seattle area.

SELECT TYPE OF CRUISING

**PARKING**

PARKING VEHICLES

SELECT DAY

**MON**

TUE

WED

THR

FRI

SAT

SUN

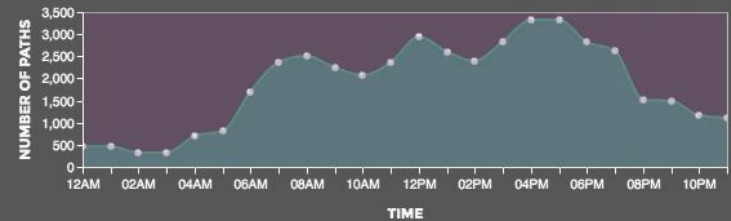
SELECT TIME

**ALL DAY**

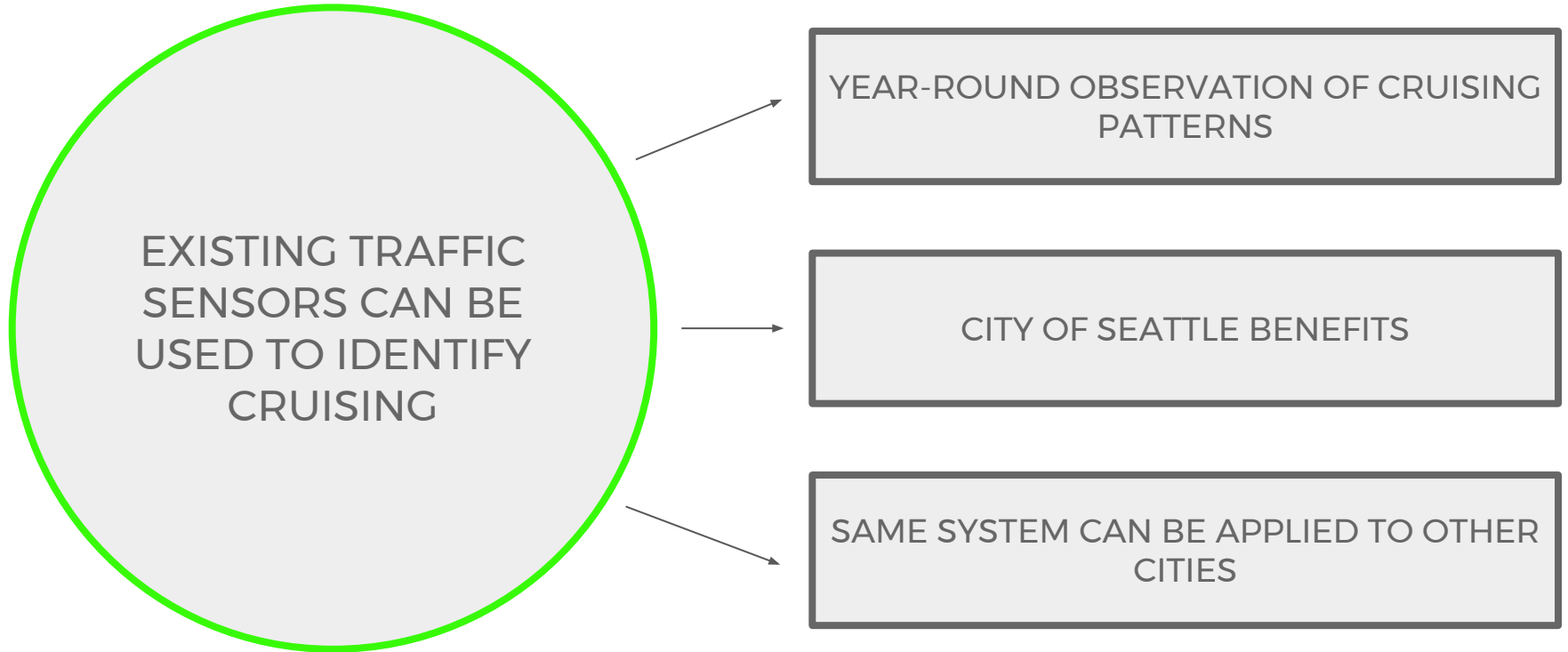
MORNING

MIDDAY

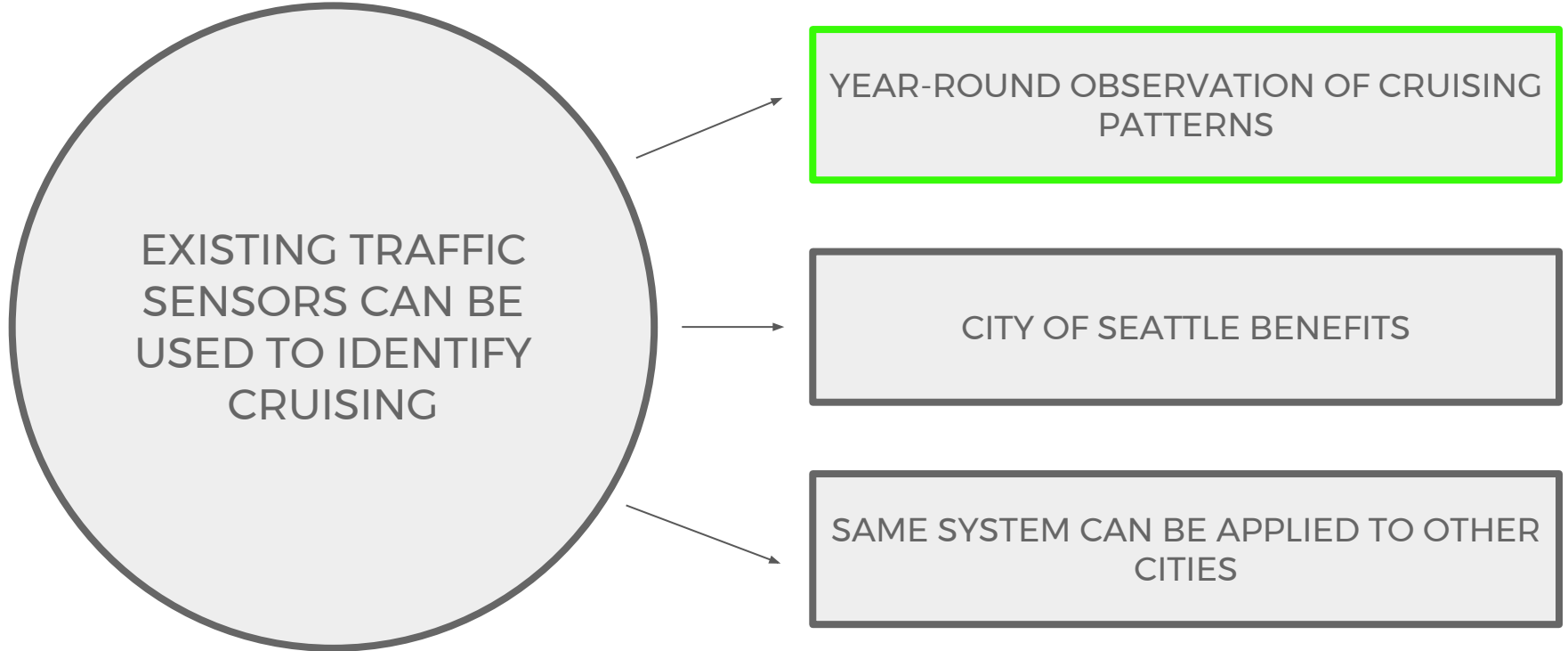
EVENING



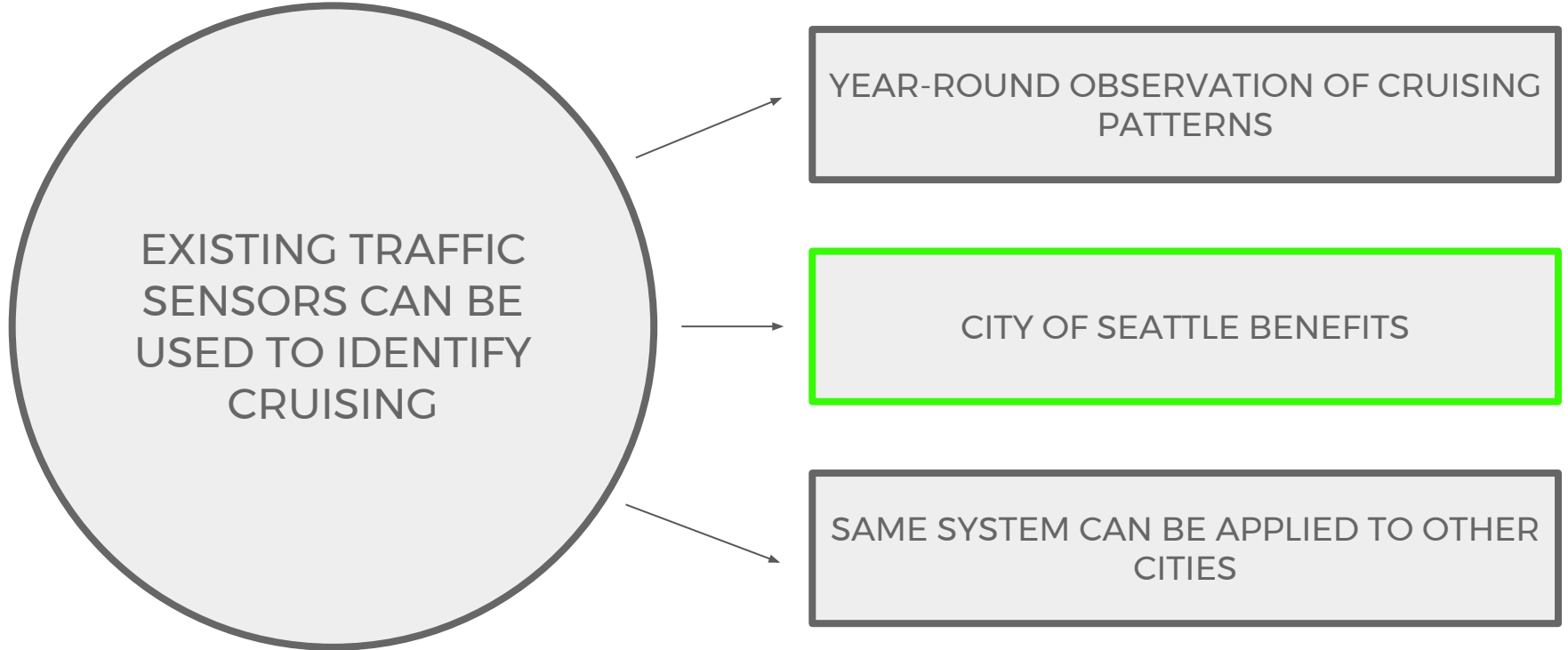
# CONCLUSION



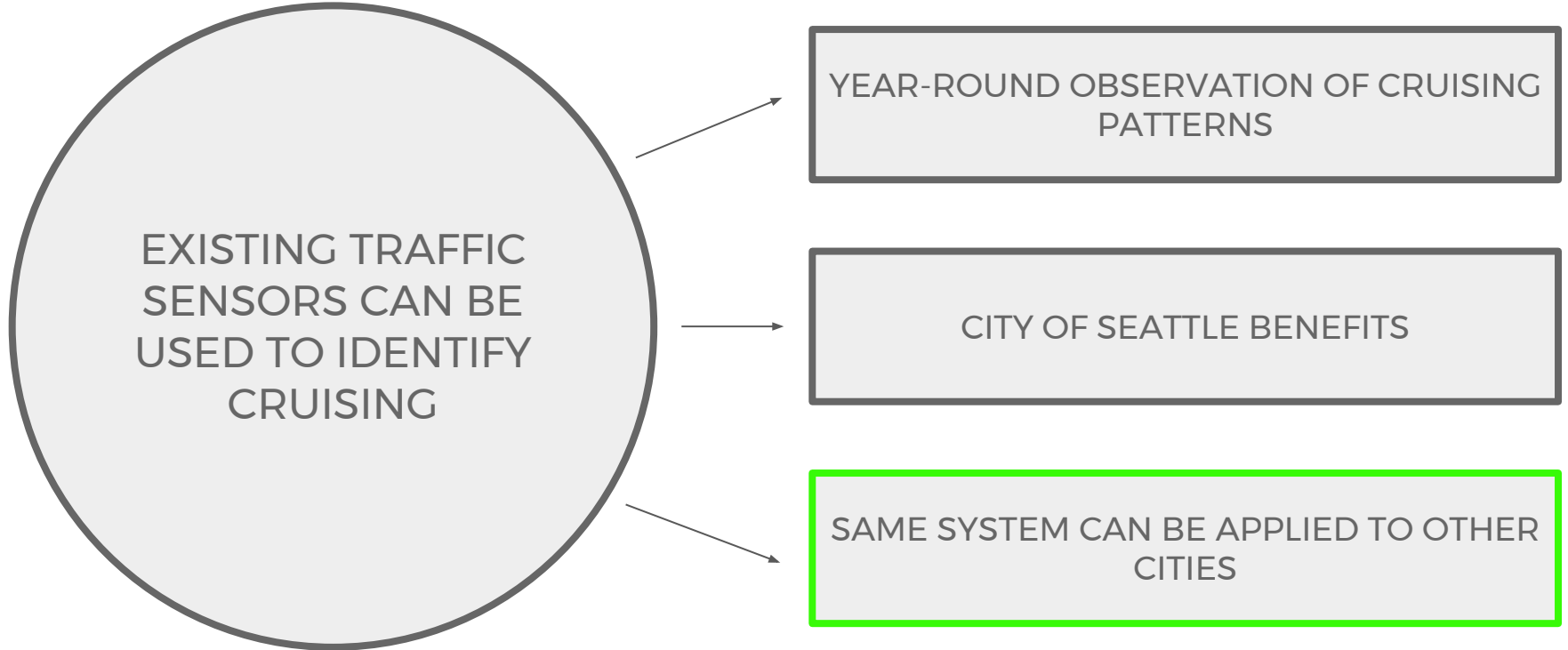
# CONCLUSION



# CONCLUSION



# CONCLUSION





Microsoft

Urban@UW



UNIVERSITY of WASHINGTON  
eScience Institute

CASCADIA URBAN  
ANALYTICS COOPERATIVE

GORDON AND BETTY  
MOORE  
FOUNDATION



Washington Research  
FOUNDATION



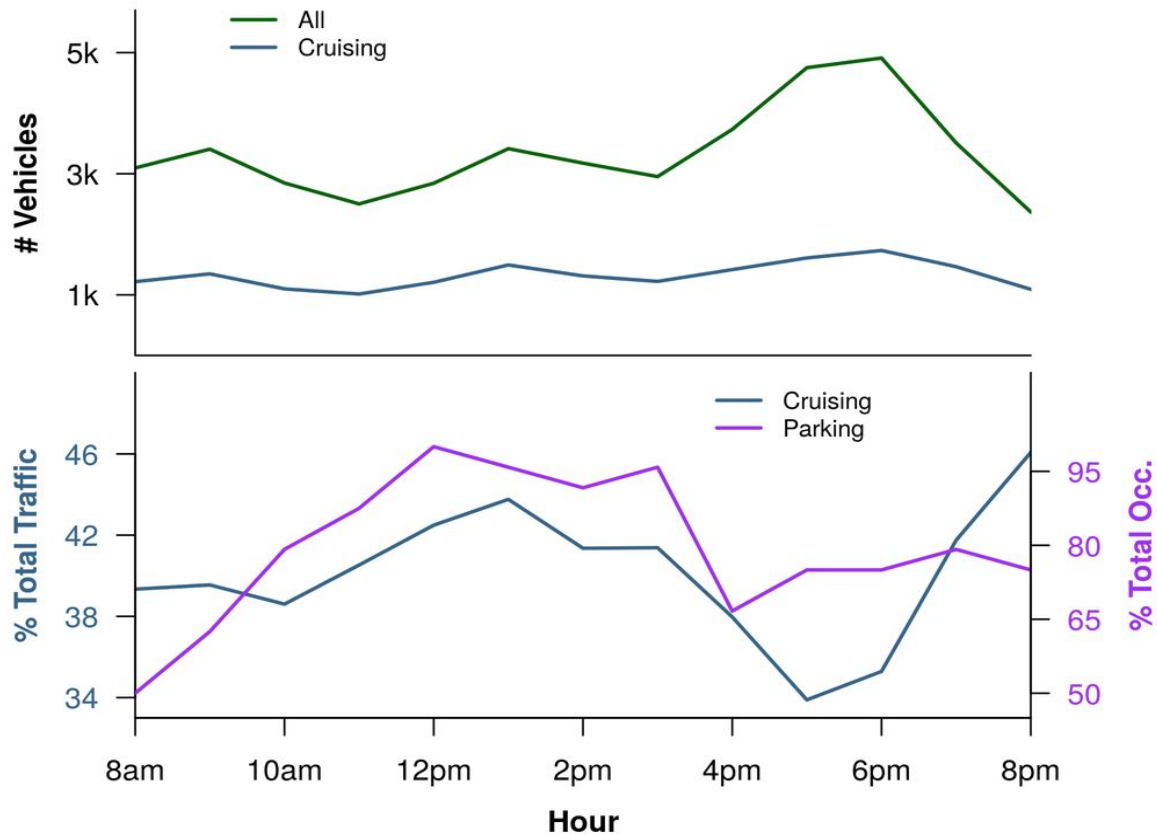
Seattle  
Department of  
Transportation



THANK YOU

QUESTIONS?

# APPENDIX



# VALIDATION

# CLASSIFICATION

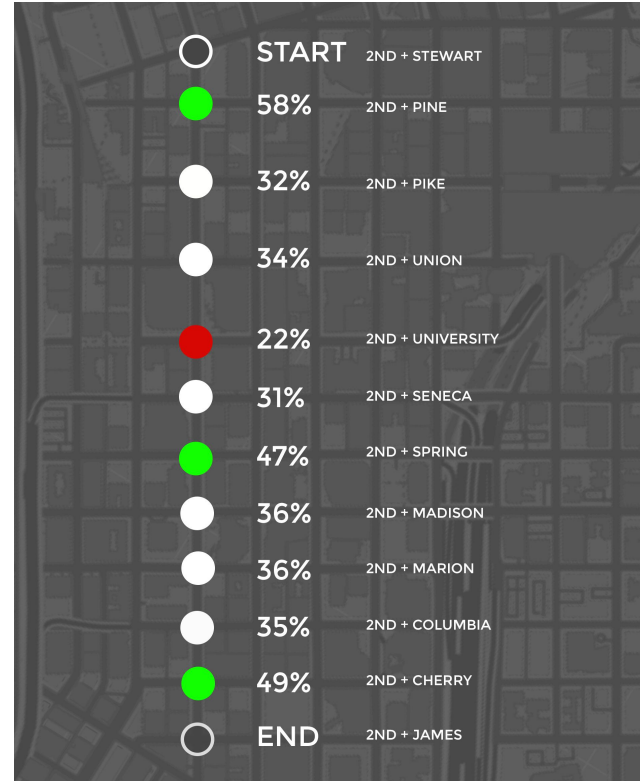
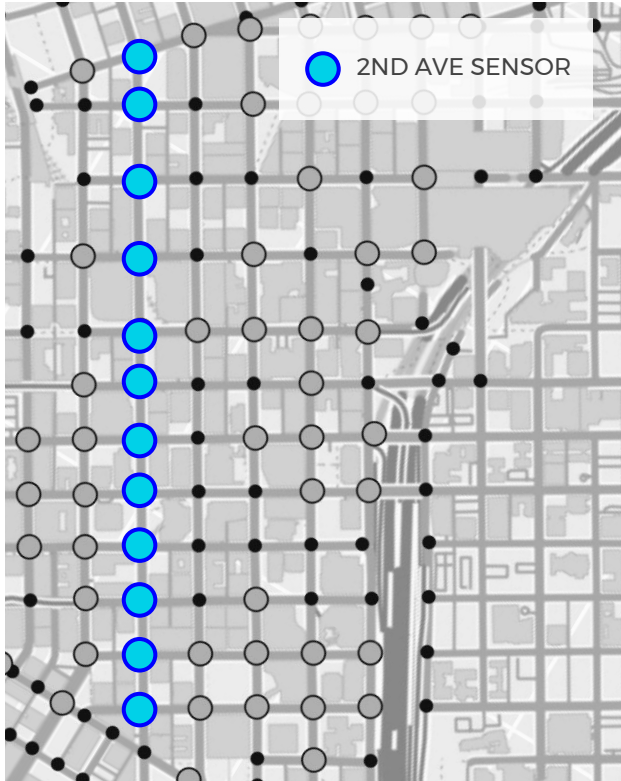
MODEL	ACCURACY	AUC_ROC	PRECISION	RECALL	F1_SCORE
DECISION TREE	0.966 +/- 0.000	0.933 +/- 0.000	0.993 +/- 0.000	0.868 +/- 0.000	0.926 +/- 0.000
LOGISTIC REGRESSION	0.925 +/- 0.001	0.870 +/- 0.001	0.921 +/- 0.001	0.762 +/- 0.001	0.834 +/- 0.001
GRADIENT BOOSTING CLASSIFIER	0.967 +/- 0.000	0.935 +/- 0.000	0.994 +/- 0.000	0.871 +/- 0.000	0.928 +/- 0.000

# FEATURE

# IMP

NUMBER OF TIMES PATH CROSSED	0.3442
AVERAGE SPEED	0.1191
PERCENTAGE OF TIME DRIVING	0.1694
HOUR	0.0101
MAXIMUM SPEED	0.0442
STD DEV OF SPEED	0.0556
STOPS 0 - 2 MIN	0.0323
STOPS 10 - 15 MIN	0.0126
STOPS 15+ MIN	0.0377
TIME PERCENTAGE CHILLING	0.0906
TIME PERCENTAGE WALKING	0.0351

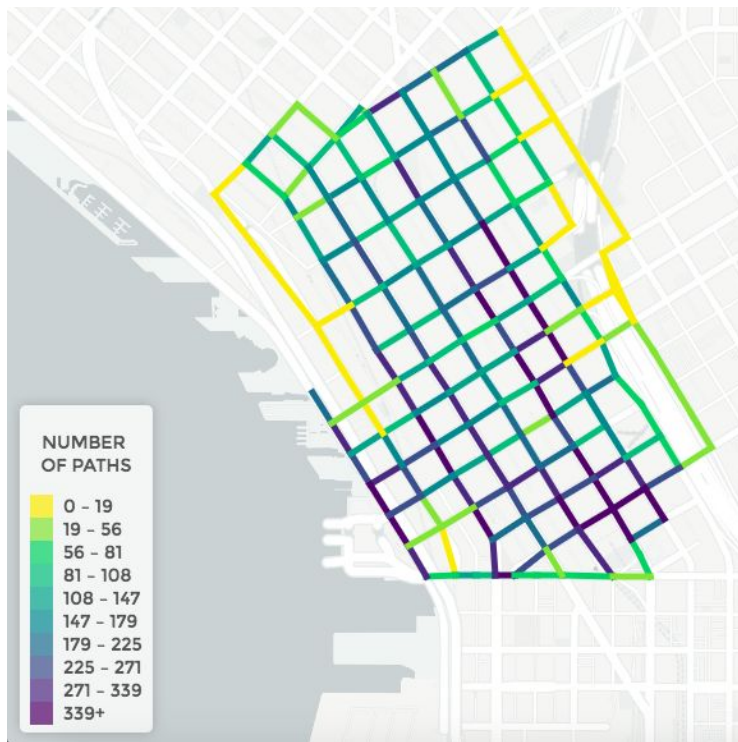
# SENSOR DETECTION RATE



PARKING

TUE

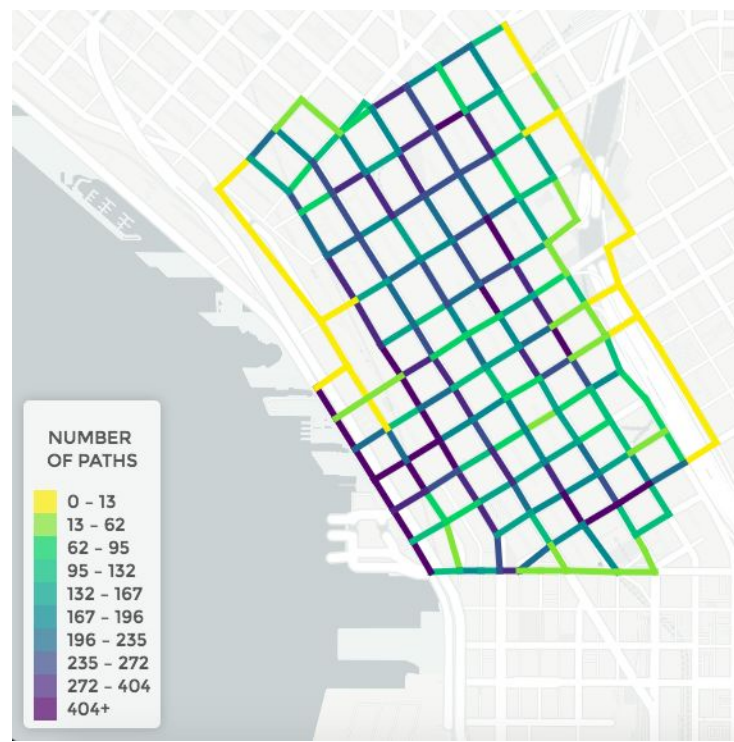
MORNING



PARKING

SAT

EVENING



# RESULTS

PARKING

TUE

MORNING



PARKING

SAT

EVENING



# RESULTS

PARKING

TUE

MORNING



PARKING

SAT

EVENING



# RESULTS