

## **MEASURING CROSSWALK SAFETY AT NON-SIGNALIZED CROSSINGS DURING NIGHTTIME BASED ON SURROGATE MEASURES OF SAFETY: A CASE STUDY IN MONTREAL**

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**1 ABSTRACT**

2 This paper proposes a methodology to evaluate crosswalk safety at nighttime using surrogate  
3 safety measures and thermal video sensors. The methodology is illustrated using two non-  
4 signalized crosswalk locations in downtown Montreal, Quebec. Video data recordings from the  
5 thermal camera were used to compare nighttime and daytime safety conditions using different  
6 surrogate safety measures including vehicle crossing speed, post encroachment time (PET), as  
7 well as the yielding compliance and the conflict rate. A new way of measuring pedestrian  
8 exposure is also proposed which excludes non-interacting road users. A thermal camera was used  
9 in an effort to alleviate issues pertaining to low visibility at night for video analysis when road  
10 users, especially pedestrians, are difficult to detect and track. The results showed that the  
11 proposed thermal-video-based surrogate safety methodology is effective to collect and analyse  
12 pedestrian-vehicle interactions at night regardless of lighting conditions. From the study  
13 crossings, results also showed that that average vehicle crossing speeds and percentage of  
14 dangerous conflicts were higher during nighttime compared to daytime, indicating that  
15 pedestrians were at higher risks during nighttime. The proposed methodology can be used to  
16 evaluate the performance of different crosswalk treatments on pedestrian safety at night.

17  
18 *Keywords:* Nighttime Safety, Crosswalk Safety, Video Analysis, Thermal Videos, Surrogate  
19 Safety Measures, Interactions, Risk Rate, Post Encroachment Time

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## 1 INTRODUCTION

2 Pedestrian safety has become a priority for many cities due to increased awareness of their  
3 vulnerability compared to other road users. In the U.S, 14 % of total road crash fatalities were  
4 pedestrians in 2013 (1). Meanwhile 15.6 % of road crash fatalities in Canada were pedestrians in  
5 2013 (2). Studies indicated that nearly half (46 %) of pedestrian fatalities in the US (3) and 57 %  
6 of pedestrian fatalities in Ontario, Canada (4) occurred at nighttime. Most crashes happen when  
7 pedestrians are crossing the streets when they are exposed to motorized traffic. A study in  
8 Europe showed that roughly 31 % of all pedestrian victims of road crashes were injured on  
9 marked crosswalks (5). Pedestrians are also vulnerable at locations with non-signalized  
10 crossings. For instance, Hunter et al. found that 40 % of intersection crashes and 93 % of  
11 midblock crashes occurred at non-signalized locations (6). Compared to daytime, there is less  
12 motorized and pedestrian traffic at nighttime, which generally leads to higher vehicle speeds as  
13 well as lower levels of driver awareness and attention. This difference in traffic and driving  
14 behavior leads to an increase in crash frequency and severity especially when pedestrians are  
15 involved (7) (8). In addition, Huang et al. point out that at nighttime, crosswalks and pedestrians  
16 can be less visible for drivers to see in time for a stop (9). Crosswalk safety has been looked into  
17 by numerous studies, and different treatments have been implemented and evaluated for different  
18 crosswalk locations; however, evaluating the safety of the treatment is challenging, in particular  
19 at night time, because of the sparse nature of the crash data and the lack of exposure measures  
20 (e.g., count data during night time). Most often, short-term counts for safety analysis are taken  
21 only during day time (10).

22 Moreover, the pedestrian safety literature has been built mainly through the use of  
23 historical crash data, focusing on crash frequency and severity as direct measures for road safety  
24 (11) (12) (13). However, vehicle-pedestrian crash data is not always available in sufficiently  
25 large quantity and suffers from known problems such as low-mean small sample, underreporting,  
26 mislocation and misclassification. Tarko et al. list the limitations of using crash data for road  
27 safety analysis (14). In addition, the low mean problem (sparse nature of the crash data) can  
28 represent a statistical issue when working with pedestrian crash data during nighttime, in which  
29 given the low level of exposure, the mean number of crashes is typically very low. Using  
30 historical data for pedestrian safety analysis requires long periods of observation (many years);  
31 thereby recent treatments cannot be quickly evaluated from crash data due to the lack of after-  
32 treatment crash data (15). In order to overcome this problem, proactive methods have been  
33 proposed that do not require waiting for crashes to happen. They rely on surrogate measures of  
34 safety that may provide better and more precise alternative road safety indicators.

35 Surrogate safety measures that rely on automated video analytics are gaining increasing  
36 popularity in road safety analysis for their various benefits (14) (15). Some studies have used  
37 such measures for identifying risk factors or evaluating treatment effectiveness using a before-  
38 after or control-case study approach (15) (16) (17) (18) (19). St-Aubin et al. developed a  
39 trajectory-based algorithm to measure Time-to-Collision (TTC) and carried out a Montreal case  
40 study to evaluate a safety treatment on highway ramps (15). This work has been extended by  
41 using realistic motion prediction methods (motion patterns learnt from observation) for the  
42 evaluation of the safety performance of roundabouts (16). Despite the important developments  
43 on surrogate safety analysis, there has been little nighttime safety evaluation using surrogate  
44 measures. Among the reasons, one can mention the technological limitations of regular video  
45 cameras (in the visible spectrum) that are unable to provide high quality data at night.

46 The objective of this work is to propose a surrogate safety methodology to quantify

1 pedestrian safety on crosswalks during nighttime using thermal video sensors. To get effective  
2 video data under nighttime conditions, this paper used a thermal-camera based system; the  
3 details of this system are reported in (20). The trajectories were then extracted from video data  
4 and analyzed by calculating speeds of crossing vehicles and Post-Encroachment Time (PET).

5 This paper begins with a literature review; it then describes the thermal camera system  
6 used to obtain usable nighttime data and measures for crosswalk safety based on video data. A  
7 case study conducted as an example of using thermal videos for crosswalk safety evaluation at  
8 night is presented. Finally, conclusions and future works are discussed.

## 9 **LITERATURE REVIEW**

10 Using traffic trajectory data obtained from video recordings is the most widely adopted method  
11 for automatically calculating surrogate safety measures. Different trackers have been developed  
12 and used to obtain trajectory data (21) (22) (23) (24) (25). Saunier et al. adapted this method to  
13 intersections to track all road users by continuously detecting new features and adding them to  
14 current feature groups (22) (23). An improved multiple object tracking system, named Urban  
15 Tracker, was developed for tracking different types of road users in urban mixed traffic (25). In  
16 addition, in order to count different road users in mixed traffic conditions and to identify  
17 interactions based on their trajectories and between different types of road users, Zangenehpour  
18 et al. developed a classification algorithm to distinguish between three types of road users:  
19 pedestrians, vehicles and cyclists (26). The proposed classifier in this study uses the occurrence  
20 area, speed distribution and presence (appearance) of the road users to classify them. The data  
21 can then be used for surrogate safety analysis of the interactions between different road users.  
22 The overall accuracy of the classification algorithm at intersections with high volumes and  
23 mixed road user traffic was approximately 93 %. This algorithm was trained for thermal video in  
24 (20) and results for mixed traffic conditions demonstrated an overall accuracy of 70 %.

25 Different studies have also used trajectory data for obtaining traffic information such as  
26 volume, speed and conflict measures, which are fundamental for surrogate safety measures (15)  
27 (16) (17) (26) (27) (28) (29). Lareshyn looked at different indicators in behavioral and road  
28 safety research in terms of validity and reliability (30), and the indicators include time to  
29 collision (TTC), post-encroachment time (PET), gap time (GP), encroachment time (ET), time  
30 headway/time gap, compliance with the yielding rules and stop sign requirements and etc.  
31 Different studies used different measures for different conditions. In (15) (16), St-Aubin et al.  
32 computed TTC using the equations presented in (30) for highway safety. Tang and Nakamura  
33 relied on PET for evaluating conflict severity at signalized intersections(31). For pedestrian  
34 safety at crosswalks, PET has been widely used (17) (29). For instance, Alhajyaseen et al. (29)  
35 used PET and vehicle speed at a crosswalk as validation parameters to assess pedestrian safety at  
36 intersections.

37 Another important concept is the exposure of pedestrian to the risk of collision with  
38 motor vehicles (32). Exposure is traditionally measured through the pedestrian and vehicle  
39 volumes passing the area of interest, i.e. crosswalks for our study, or their product. But exposure  
40 is a general concept that represents the opportunities or necessary conditions for a collision to  
41 occur: it can be measured in various ways which depend on the purpose of the study. Pedestrians'  
42 exposure was already used in 1989 in a study of pedestrian safety at traffic signals using a  
43 manual traffic conflict technique (TCT) (33). In 1998, Silcock et al (34) proposed a method that  
44 used video recording as a data collection method to automatically extract data from video tapes  
45 describing the number of crossing movements and pedestrian-vehicle interactions. However, the  
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1 definition of the conflicts (e.g. the threshold used on the surrogate measure of safety to  
2 distinguish from other events) was not clarified (35). Exposure is generally used to calculate  
3 pedestrian risks of collision with vehicles through crash or conflict ratios. The ratio is calculated  
4 based on the number of crashes or conflicts over the total exposure, which reflects the probability  
5 dimension of risk, i.e. the probability of a crash or conflict per unit of the chosen exposure. The  
6 most recent work using surrogate safety analysis with rate calculations can be found in (26). In  
7 this paper, the authors used the ratio of the total number of conflicts and severe conflicts divided  
8 by the product of the pedestrian and vehicle volumes. Other indicators such as speed and  
9 yielding compliance to evaluated crosswalk safety have been used extensively in similar studies.

10 Different measures of pedestrian exposure have been proposed (35). In the literature, the  
11 number of pedestrian crossings (per hour), vehicle volume, or their product have been used as  
12 the key indicators; however, these measures do not correspond to events where a pedestrian and  
13 a vehicle may actually interact, i.e. they are close enough to each other at the site of interest that  
14 they are at least aware of each other. There is a huge gap between the product of traffic volumes  
15 and an actual interaction between a pedestrian and a vehicle. This gap is even larger during  
16 nighttime in which pedestrian and vehicle flows are much lower and can present more temporal  
17 variability. Vehicle-pedestrian interactions change from site to site and from time to time due to  
18 many conditions at different sites. Besides, upstream signalization has a large impact on the  
19 arriving time of the pedestrians and the vehicles, which also influences pedestrian exposure. All  
20 these uncertainties may explain the low or unreported model fitness in past studies. All these  
21 require proposing and testing existing and new exposure measures.

## 22 **METHODOLOGY**

23 The methodology consists of three key steps: thermal video data collection, trajectory extraction,  
24 and computation of surrogate safety measures.

### 25 **Thermal Video System, Object Tracking and Validation of Detection Performance**

26 A thermal camera system was used for data collection. For details about the system and its  
27 performance in nighttime conditions, one can refer to (20). The system components are presented  
28 in **FIGURE 1 a)**. For field measuring purposes, the camera was mounted on an adjustable mast  
29 against existing poles (i.e. lamppost or telephone pole) with an ideal coverage area and camera  
30 angle. **FIGURE 1 b)** shows a sample snapshot from the thermal video which was taken at  
31 nighttime where regular cameras in the visible spectrum fail to provide enough details about road  
32 users because of the darkness, reflection, and shadow and glare from different light sources.  
33 **FIGURE 1 c)** presents the issues of using regular videos for video data collection at night, and  
34 how thermal video is not affected by these lighting issues.

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**FIGURE 1 Thermal camera system and a comparison with regular videos at nighttime**

Once video was collected, video data processing was carried out using the tracker in the open source Traffic Intelligence project (22); as an outcome, road user trajectories were obtained. The techniques used in the tracker are explained by Shi and Tomasi (21) and Saunier(23). (20) has validated the performance of video analysis using thermal video for traffic data collection in multi-modal environments in various lighting and temperature conditions, and has shown the reliability of this technique. Compared with mixed traffic conditions at intersections, non-signalized crosswalks are much simpler because road users travel in fixed directions along fixed segregated paths. Therefore, the performance of the tracker for detecting road users at crosswalks is expected to be higher. This study uses the performance measures introduced in (20). Miss rate was defined in (20) as “the proportion of road users whose movement is not captured by any trajectories”, and “was used to quantify detection performance. For pedestrians, the detection performance was evaluated at the group level, i.e. a group of pedestrians not tracked is counted as one miss”. Precision and recall for detection are also reported.

## 1 Safety Measures

2 For evaluating the safety status of a crosswalk during night time, the following three measures  
3 were defined.

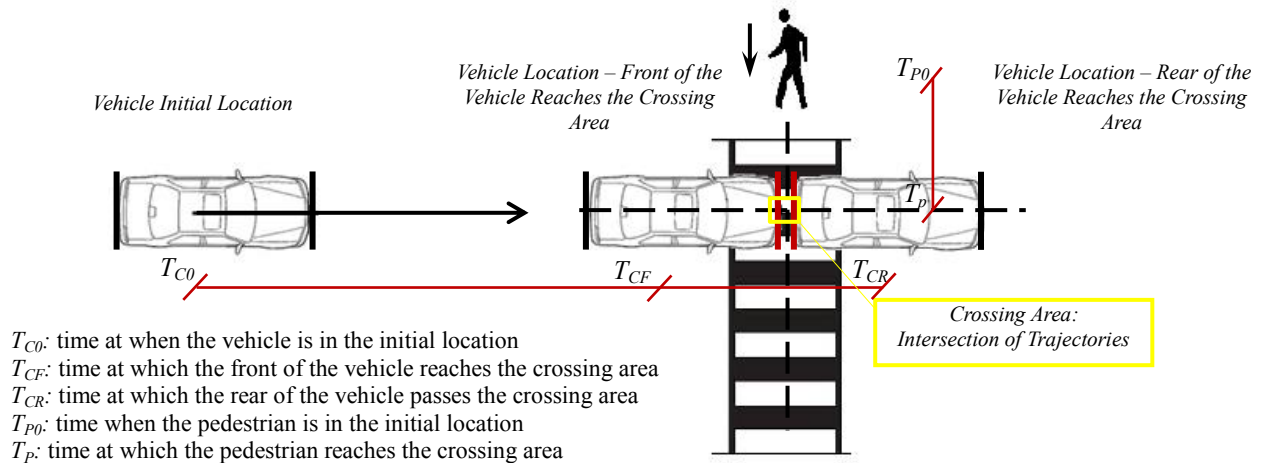
### 4 Pedestrian-Vehicle Interaction

5 **FIGURE 2** describes an interaction between a pedestrian and a vehicle at a crosswalk. PET is  
6 defined as “the time gap” between two road users “arriving” and “leaving” the crossing area;  
7 PET is used in this study as the surrogate safety measure for interactions between pedestrians  
8 crossing the street and vehicles since their trajectories will always intersect and PET can thus  
9 always be computed. The fact that PET may not be computed for some interactions is otherwise  
10 a known shortcoming of that measure. Based on the road user classification and the trajectory  
11 data of each road user, the PETs of pedestrian-vehicle interactions is calculated as:  
12

$$13 \quad PET = \begin{cases} T_{CF} - T_P, & \text{if } T_P < T_{CF} \\ T_P - T_{CR}, & \text{if } T_{CR} < T_P \end{cases} \quad (1)$$

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15  
16 Where the notations are defined and illustrated in **FIGURE 2**:  $T_P < T_{CF}$  indicates the situation  
17 where the pedestrian arrives at the crossing area before the vehicle, while  $T_{CR} < T_P$  means the  
18 opposite. The study used the trajectory data to measure the PET between each pedestrian  
19 crossing the street and vehicle crossing the crosswalk at a same time. This study used a computer  
20 vision safety analysis tool to automatically calculate the PET values for each pair of interacting  
21 vehicle and pedestrian. Interactions with PETs less than 5 seconds were considered as conflicts,  
22 and those with PETs less than 1.5 seconds were defined as dangerous conflicts. For details about  
23 the PET thresholds for the conflicts, see (19). With the computer vision software, pedestrians  
24 may be tracked in a group, in which case only one interaction with the whole group will be  
25 counted - in real situation, a small group pedestrians walking together could be regarded as one  
26 road user as they have the same chance in interactions with passing vehicles.

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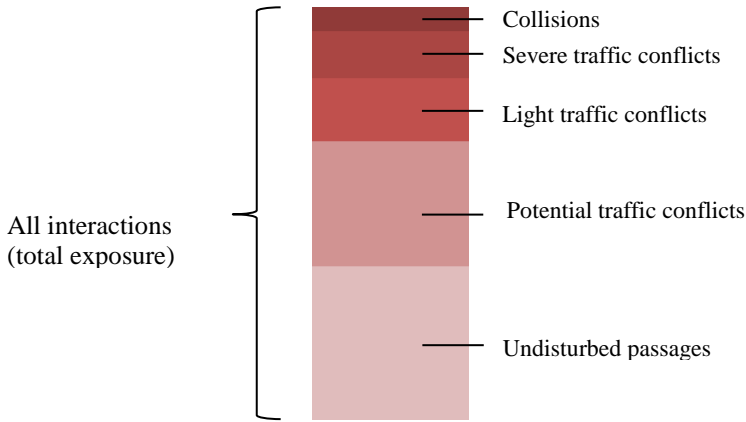
**FIGURE 2 Description of pedestrian-vehicle interactions at a crosswalk**

### 34 Pedestrian Exposure Measure

35 Exposure measures, in most of the literature, are based on traffic volumes. Different exposure

1 measures can be used depending on the purpose and can be considered in the traditional safety  
 2 hierarchy framework of surrogate safety analysis based on earlier work by Hydén among others  
 3 **(36)** illustrated in **FIGURE 3**, with collisions as the most severe events at the top and  
 4 undisturbed passages at the bottom. Using microscopic trajectory data, this work can measure  
 5 exposure at the level of road user interactions, when two road users are close enough in time and  
 6 space. This paper sets an arbitrary threshold of 20 s on PET for interactions considered as  
 7 exposure to pedestrian-vehicle collisions.

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11 **FIGURE 3 Pedestrian-vehicle interactions in the safety hierarchy (36)**

12

13 *Safety Measures*

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15 Safety measures are analyzed by visualizing the cumulative distribution functions (CDFs) and  
 16 the interaction rate based on the exposure measure defined above: this paper calculates the  
 17 interaction rate at crosswalks as the number of conflicts over the number of interactions used as  
 18 exposure.

18

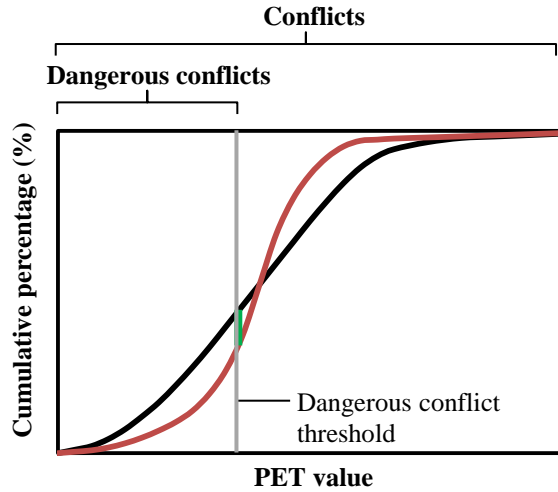
19 **Cumulative Distribution Functions (CDFs)**

20

21 Visualization has been proved to be powerful for comparison purposes. CDFs are used in this  
 22 study as a way to understand pedestrian risk at crosswalk. **FIGURE 4** demonstrates the principle  
 23 of this analysis method. The elevated line indicates a higher proportion of dangerous conflicts.  
 24 The grey line in the figure represents the dangerous conflict threshold and the right border of the  
 25 figure is the conflict threshold. This method of showing safety is intuitive; however, as **(37)**  
 26 illustrated, using cumulative distribution is not always conclusive.

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3 **FIGURE 4 Illustration of different cumulative distribution functions**

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5 **Conflict Ratio**

6 Two conflict rates are used. For a given site  $i$ , the conflict rate ( $R_{Ci}$ ) is defined as the number of  
7 pedestrian-vehicle conflicts, which are the interactions with PETs less than 5 s, divided by the  
8 number of interactions with PET less than 20 s denoted  $N_{Ei}$  (exposure). The dangerous conflict  
9 rate ( $R_{DCi}$ ) is defined as the number of dangerous conflicts, which are the interactions with PET  
10 less than 1.5 s, divided by the same exposure measure  $N_{Ei}$ .

11  
12 *Other Safety Measures: Crossing Speed and Yielding Compliance*

13 **Crossing Speed**

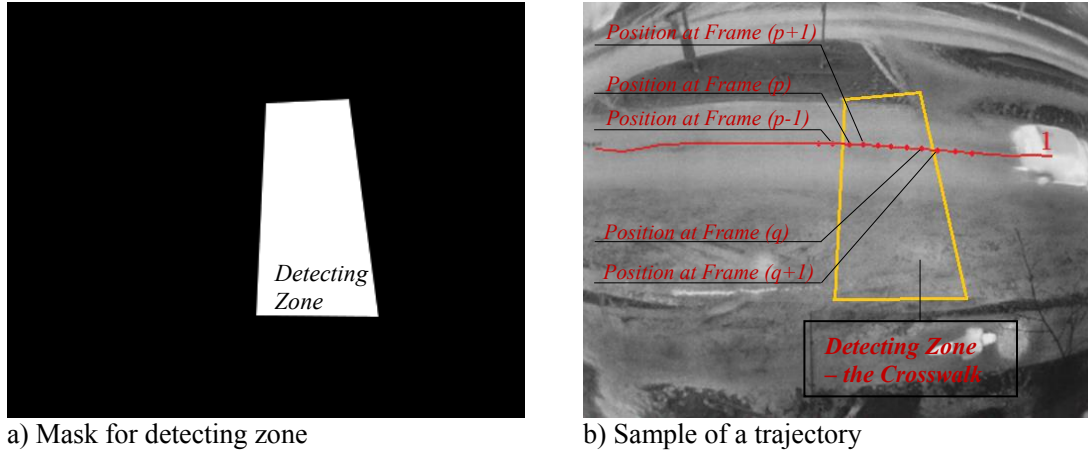
14 The crossing speed of vehicles passing the crosswalk was used as a safety measure in this paper.  
15 Crossing speeds were automatically extracted from the videos through the computer vision  
16 software and have been shown to be reliable in (20). A script was used for extracting velocities  
17 and calculating the speeds for vehicles passing the crosswalk. **FIGURE 5** presents how the  
18 crossing speeds were extracted. A mask was prepared for the detection zone – the crosswalk in  
19 this case, shown in **FIGURE 5** a). In video collected from site  $i$ , for a certain vehicle  $j$ ,  $j =$   
20  $(1, \dots, N)$ , where  $N$  is the total number of vehicles, if its trajectory falls in the detecting zone in  
21 video frame  $m$ ,  $m \in (p, p + 1, \dots, q)$ , its velocity  $\overrightarrow{v_{ijm}}$  is extracted and the instantaneous speed  
22  $s_{ijm}$  is calculated. The crossing speed is calculated by averaging the instantaneous speeds in  
23 these frames, as presented in the following equation:

24  
25 
$$s_{ij} = \frac{1}{q-p+1} \sum_{m=p}^q (s_{ijm}) \quad (2)$$

26  
27 The average crossing speed for site  $i$  would be:

28  
29 
$$s_i = \frac{1}{N} \sum_{j=1}^N (s_{ij}) \quad (3)$$

30  
31 Speed distributions and average crossing speeds of all the passing vehicles were compared.  
32



a) Mask for detecting zone

b) Sample of a trajectory

**FIGURE 5 Sample of speed extraction through the computer vision software****Yielding Compliance**

The law requires vehicles to yield to a pedestrian when he is starting or indicating the intention to cross the road. In this case, yielding compliance refers to the rate of drivers' yielding behavior among the pedestrian-vehicle interactions which require the drivers to slow down or stop to give pedestrians the right-of-way. Yielding compliance rate (*YCR*) was calculated by manually counting the vehicle yielding maneuvers. For site  $i$ , if a pedestrian arrives at the crosswalk before a certain vehicle  $j$ , the yielding behavior of this vehicle involved in an interaction with a pedestrian can be quantified by the following measures

$$X_{ij} = \begin{cases} 1 & \text{if the vehicle yields and gives right of way to the pedestrian} \\ 0 & \text{otherwise} \end{cases}, j = (1, \dots, M_i) \quad (4)$$

$$Y_i = \sum_1^M X_{ij} \quad (5)$$

$$YCR_i = \frac{Y_i}{M_i} \quad (6)$$

Where  $M_i$  is the total number of interactions between the crossing vehicle and the pedestrian already starting or indicating his intention to cross and, to avoid a collision, at least one involved road user must yield.  $Y_i$  is the total number of yielding drivers and  $YCR_i$  is the yielding compliance rate.

**Validation of the Classification Tool for Pedestrian-Vehicle Interactions at Crosswalks**

In order to calculate the PETs, a classification method is required to identify the vehicle-pedestrian interactions. A modification of a previously developed method for object classification in video (26) was used in this study. The modification was done by changing the image database for detecting road user presence in thermal videos (20). One can refer to (26) and (20) for details. **FIGURE 6** presents a sample snapshot of tracking and classification results.

In (20), the overall accuracy of the classification algorithm in terms of classification performance measures has been shown to be over 80 % for mixed traffic with the average precision of 70.9 % and the average recall of 99.5 % for vehicles, the average precision of 73.2 % and the average recall of 89.2 % for cyclists and the average precision of 98.6 % and the

1 average recall of 72.0 % for pedestrians. While the rates are relatively high, they are not high  
 2 enough to conduct a safety analysis. However, with the simpler traffic conditions at non-  
 3 signalized crosswalks, the performance of classification algorithm is expected to be better.  
 4 Similarly to (20), the classification performance was validated in terms of precision, recall and  
 5 overall accuracy, and was measured by extracting frames at every 10 consecutive seconds of  
 6 video.  
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10 **FIGURE 6 Tracking & Classification process with video - Sample of tracking and**  
 11 **classification. The red line represents the trajectories of the moving objects up to the time**  
 12 **of the image; P stands for pedestrians and C stands for cars**

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## 14 CASE STUDY

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### 16 Site Selection and Data Description

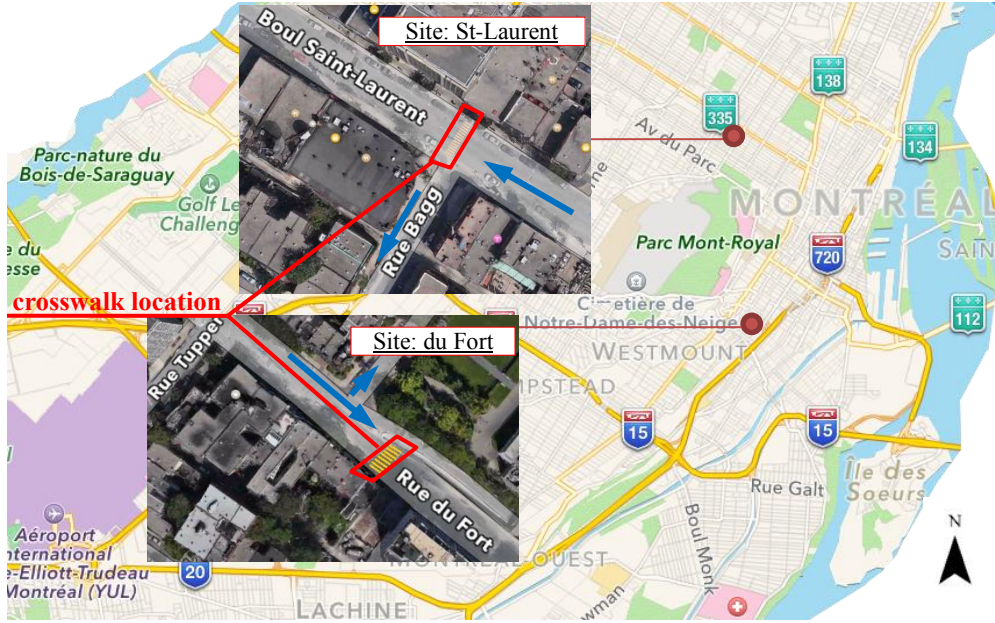
17 **FIGURE 7** shows the locations of the selected sites. For testing the thermal camera system and  
 18 investigating the crosswalk safety, two crosswalk locations with different traffic and  
 19 environmental conditions were selected in downtown Montreal:

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21 • **Site du Fort:** This crosswalk is located on Rue du Fort at the intersection of Rue du Fort  
 22 and Rue Baile. It is a painted crosswalk crossing two one-way lanes and a median  
 23 between the two lanes. Since the left lane was observed to have very little traffic, only the  
 24 right lane was analyzed. Located on a secondary road, this site has a relatively low traffic  
 volume.

25

26 • **Site St-Laurent:** The crosswalk is located on one of the main arteries in downtown  
 27 Montreal, Boulevard St-Laurent, at the intersection of Boulevard St-Laurent and Rue  
 28 Bagg. It is a painted crosswalk crossing two one-way lanes. This location is busier than  
 29 the du Fort site in terms of vehicular and pedestrian traffic.





**FIGURE 7 Locations of the selected sites**

For each site, thermal video data were collected in both daytime and nighttime conditions. A total number of 16.8 hours of video data were collected. For comparison purposes, all video data were collected in the same season with similar traffic, weather and road surface conditions (i.e. collected on good weather conditions with bare pavement in winter). All the videos were recorded during the afternoon peak period and at nighttime on weekdays when higher crash rates were observed. Details of the video data are presented in Table 1.

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1 **TABLE 1 Description of the Video Recorded from Each Site**

Site name	du Fort	St-Laurent		
Camera View				
Total hour collected at night	4.6 hrs	6.0 hrs		
Total hour collected during the day	2.6 hrs	3.6 hrs		
Site name	Date	Period of a Day	Time	Duration (hour)
du Fort	11-Nov-2014	Day	03:00-04:40pm	1.6
		Night	07:00-08:15pm	1.2
	14-Jan-2015	Night	06:30-08:20pm	1.8
	15-Jan-2015	Day	03:30-04:30pm	1.0
		Night	07:00-08:40pm	1.6
St-Laurent	31-Dec-2014	Day	03:00-04:10pm	1.2
		Night	06:30-09:15pm	2.8
	01-Jan-2015	Day	02:00-04:30pm	2.4
		Night	06:00-09:15pm	3.3

3

4 **Detection and Classification Validation**

5 The tracker and the classification algorithm were validated using 30 minute video samples from  
6 each site. Results of the detection and classification performance are provided in Table 2.

7

8 **TABLE 2 Classification Accuracy Validation Results**

	No. of Presence	No. of Missed /Miss Rate	Detection Performance		Classification Performance	
			Precision	Recall	Precision	Recall
<b>du Fort (Video length of 30 minutes, from night, 14-Jan-2015)</b>						
Vehicle	68	1 / 1.7%	97.1%	97.1%	98.5%	98.5%
Pedestrian	60	1 / 1.6%	100%	81.1%	100%	98.3%
Overall	128	2 / 1.6%	91.4%	98.4%	Global Accuracy = 97.7%	
<b>St-Laurent (Video length of 30 minutes, from night, 31-Dec-2014)</b>						
Vehicle	205	0 / 0%	97.6%	98.6%	94.8%	97.6%
Pedestrian	104	1 / 1.0%	100%	80.0%	100%	93.0%
Overall	309	1 / 0.3%	93.1%	98.4%	Global Accuracy = 91.7%	

9

10 Based on the results, the tracker and the classification algorithm worked almost perfectly  
11 in detecting and classifying the pedestrians and vehicles at each crosswalk – very few misses and

1 around 95 % of precision, recall and global accuracy rates in most cases, except for the lower  
2 recall values in detecting pedestrians (around 80 %) mainly resulting from the over-grouping of  
3 pedestrians moving together (20). These values are much higher than those for mixed traffic  
4 tested in (20), indicating the reliable performance of using the tracker and the classification  
5 algorithm at crosswalks. The small portion of the misclassified road users could be easily  
6 corrected in the output SQLite file.

## 8 Results and Analysis

9 The proposed methodology was applied to the selected sites and video data were processed.  
10 Mean vehicle speed over the vehicle trajectory within the marked crosswalk area was calculated  
11 as the crossing speed for each vehicle, and PETs between vehicles and pedestrians were  
12 computed. For the du Fort site, an average of 319 vehicles and 161 pedestrians per hour were  
13 detected during the 2.6 hours of video data collected in daytime conditions while a volume of  
14 414 vehicles and 127 pedestrians per hour were detected from the 4.6 hours of video taken at  
15 night. The St-Laurent site had a volume of 848 vehicles and 994 pedestrians per hour during 3.6  
16 hours of daytime video recordings, and a vehicle flow of 833 vehicles and 407 pedestrians per  
17 hour during 6.1 hours of nighttime video recordings. Table 3 presents a summary of the results of  
18 different safety measures, which includes the vehicle crossing speed, vehicle yielding  
19 compliance rate, exposure measured in the traditional way using the product of pedestrian and  
20 vehicle volume, number of the conflicts, conflict rate, number of dangerous conflicts and rate of  
21 dangerous conflicts, for both sites. **FIGURE 8** presents the distributions of speeds and the CDFs  
22 of PET for conflicts for both day and night.

23 Looking at **FIGURE 8 a)** and **c)** it can be observed that increases in the crossing speed  
24 were detected at night for both sites. Also, from Table 3, for the crosswalk safety situation, the  
25 average crossing speeds were found to be higher (by 9.3 % - 16.8 %) at the crosswalk of the du  
26 Fort site at nighttime compared to daytime; for the St-Laurent site, the average crossing speeds  
27 increase by around 30 % at night compared to daytime. Possible reasons for this observation  
28 could be: 1) although the traffic flow is similar between afternoon peak hours and early nighttime  
29 hours for both sites, the volumes at the second site are higher during the afternoon peak hours,  
30 which leads to the congestion of the adjacent road segments; 2) during the afternoon peak hour, a  
31 large number of vehicles are searching for parking spots and their parking maneuvers block the  
32 traffic. This phenomenon is especially evident for the site of St-Laurent, where a pharmacy and  
33 many restaurants are located. Many parking maneuvers were observed in the daytime while  
34 fewer occurred at night; 3) Because of lower traffic volumes and less pedestrian activity at night,  
35 drivers drive faster. This increase in the average crossing speeds of the passing vehicles at the  
36 crosswalks at nighttime indicates that pedestrians are exposed to higher probabilities of severe  
37 crashes at night.

38 Exposure was measured in both the traditional way using the pedestrian-vehicle volume  
39 product and the exposure using PET. The ratio of the “real” exposure number over the second  
40 definition was calculated to compare the exposure measures in different situations. From Table 3,  
41 most of the values were less than 1 and these ratios actually varied from case to case. The  
42 exposure of the number of interactions with PET less than 20 s is used in the study to compute  
43 the rates and evaluate the safety performance. From the results, a higher exposures can be  
44 observed in daytime compared to nighttime in most cases except for data collected at the du Fort  
45 site on Wednesday, January 14<sup>th</sup> when a hockey game brought about a large number of people at  
46 nighttime, and data collected from the St-Laurent site on Thursday, January 15<sup>th</sup> when people



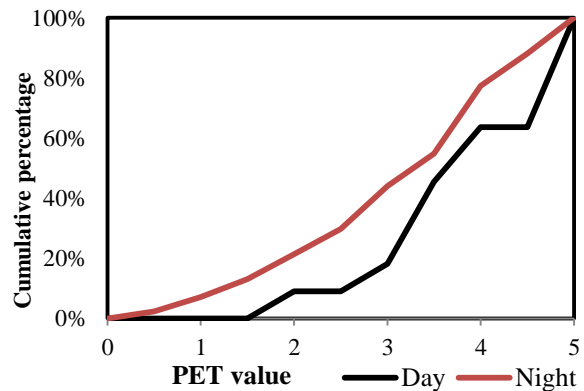
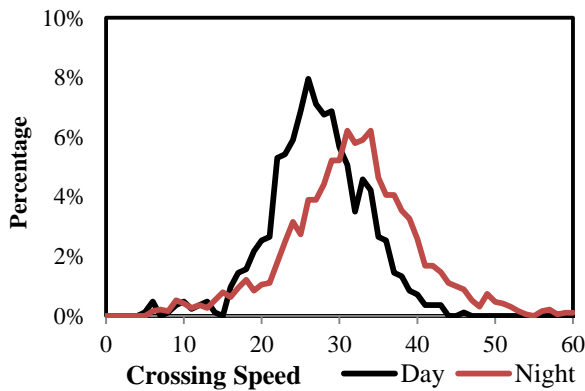
1 went out clubbing.

2 From **FIGURE 8 b)** and **d)**, among all interactions, a higher percentage of dangerous  
 3 conflicts (with PET less than 1.5 seconds) were observed at nighttime compared to daytime,  
 4 which indicates that pedestrians were involved in more dangerous interactions with vehicles at the  
 5 crosswalks at night. Looking at the rates,  $R_C$  values do not necessarily change from daytime to  
 6 nighttime, while the  $R_{DC}$  values indicate that pedestrians experience higher risks of being involved  
 7 in a dangerous conflict at night.

8 These results concerning the speeds and conflict rates seem to indicate that at these two  
 9 locations, pedestrians were at higher risks of being involved in a dangerous interaction at night,  
 10 when crossing speeds were on average higher.

11 However, regarding the yielding behavior of the drivers, people’s yielding compliance  
 12 varies from site to site. Site du Fort had a higher yielding rate at nighttime, while the yielding  
 13 rate is reduced at night at site St-Laurent. Upon a field inspection on Rue du Fort, in daytime,  
 14 vehicles were parked near the crosswalk along the sidewalk, which was free of parked vehicles at  
 15 night. This observation might explain the increase in yielding rate at night at this site as  
 16 pedestrians were easier to detect in advance by drivers. Regardless the results indicated overall  
 17 that the yielding compliance of the drivers at these two locations were both low (on an average  
 18 of 15 % - 38 % for the two sites).

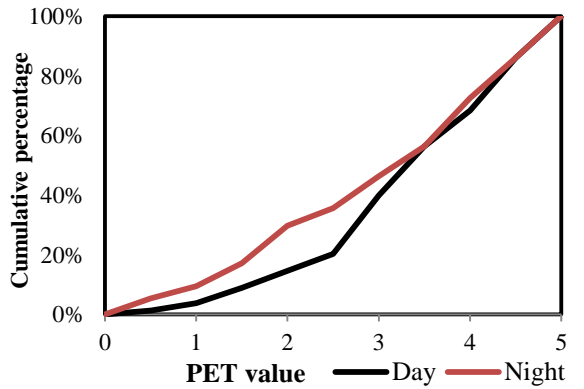
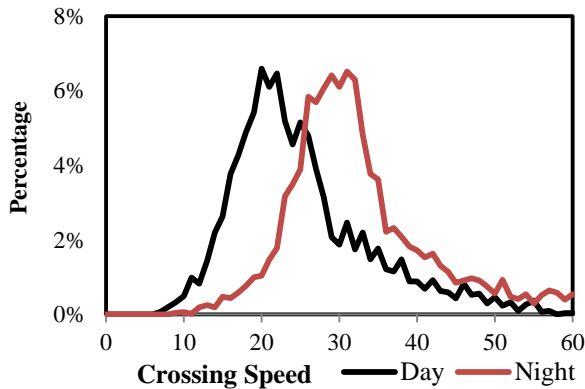
19



20

21 a) Speed distribution – du Fort

b) Cumulative conflict distribution – du Fort



22

23 c) Speed distribution – St-Laurent

d) Cumulative conflict distribution – St-Laurent

24

25 **FIGURE 8 Visualization results of the two sites – speed distributions and PET CDFs**

1 **TABLE 3 Results - Exposure Measures and Other Safety Measures for Daytime VS. Nighttime**

2

	Date	Day	Night	Day	Night	Day	Night	Day	Night
		<i>Vehicle Volume (vph)</i>		<i>Pedestrian Volume (pph)</i>		<i>Average Cro. Speed (km/h)</i>		<i>Yielding Compliance</i>	
<b>du Fort</b>	13-Nov-14	359.4	439.2	53.8	23.3	27.95	30.57	20.83%	50.00%
	14-Jan-15	--	469.4	--	167.8	--	31.22	--	38.52%
	15-Jan-15	331.9	255.0	160.6	127.0	26.56	30.78	11.76%	18.18%
	<i>all</i>	319.2	413.7	81.9	127.6	26.68	31.17	15.52%	37.66%
<b>St-Laurent</b>	31-Dec-14	1333.3	629.3	1087.5	423.2	24.42	32.02	32.69%	18.18%
	01-Jan-15	605.0	1005.8	946.7	392.7	24.97	33.74	30.11%	25.40%
	<i>all</i>	847.8	833.0	993.6	406.7	24.68	33.84	31.47%	22.92%
		<i>Traditional Exposure (per hour)</i>		<i>Number of Interactions with PET &lt; 20 s (exposure) (per hour)</i>		<i>No. Interactions/Trad. Exposure (per thousand)</i>			
<b>du Fort</b>	13-Nov-14	19316	10247	126.9	114.2	6.6	11.1		
	14-Jan-15	--	78762	--	517.2	--	6.6		
	15-Jan-15	53307	32385	213.1	208.0	4.0	6.4		
	<i>all</i>	26152	52791	158.1	306.3	6.0	5.8		
<b>St-Laurent</b>	31-Dec-14	1450000	266323	6129.2	1758.9	4.2	6.6		
	01-Jan-15	572733	394988	3659.2	5280.9	6.4	13.4		
	<i>all</i>	842361	338779	4531.9	3664.3	5.4	10.8		
		<i>No. Conflicts</i>		<i>Conflict Rate</i>		<i>No. Dangerous Conflicts</i>		<i>Dangerous Conf. Rate</i>	
<b>du Fort</b>	13-Nov-14	2.5	5.0	1.97%	4.38%	0.0	0.0	0.00%	0.00%
	14-Jan-15	--	36.1	--	6.98%	--	3.9	--	0.75%
	15-Jan-15	9.0	8.1	4.22%	3.89%	0.0	2.5	0.00%	1.20%
	<i>all</i>	5.0	18.3	3.16%	5.97%	0.0	2.4	0.00%	0.78%
<b>St-Laurent</b>	31-Dec-14	55.8	27.1	0.91%	1.54%	5.0	2.9	0.08%	0.16%
	01-Jan-15	37.9	44.2	1.04%	0.84%	3.3	9.1	0.09%	0.17%
	<i>all</i>	43.9	36.4	0.97%	0.99%	3.9	6.2	0.09%	0.17%

3



## 1 CONCLUSION

2 This paper presented an automated video-based methodology for safety analysis for pedestrian  
3 crossings at nighttime. This method was based on the use of thermal video sensors for recording  
4 video in nighttime. The preliminary results showed that pedestrians were exposed to higher risk  
5 levels at the study sites in nighttime as opposed to daytime conditions. The proposed automated  
6 methodology can be implemented for assessing different crosswalk treatments, such as LED  
7 pedestrian warning signs, an automated pedestrian detection-warning system and  
8 geometric/markings treatments for improving crosswalk safety at nighttime. Results from this  
9 paper showed that at the studied non-signalized pedestrian crossings, the average vehicle  
10 crossing speeds are higher and percentage of dangerous conflicts were higher during nighttime  
11 compared to daytime, indicating that pedestrians were at higher risks during nighttime. Not much  
12 difference was found concerning the yielding compliance and the conflict rate; however, in both  
13 sites the yielding compliance rate was quite low.

14 Thermal camera sensors provide a reliable solution to the limitation of common video  
15 sensors in the visible spectrum when used for nighttime analysis. The main advantage of using  
16 thermal cameras over regular ones is their ability to collect useful, high-quality and reliable data  
17 under different environmental conditions such as in instances of low visibility and the presence  
18 of glare or shadows caused by different light sources. Though the unit price of the thermal  
19 camera is relatively high, rapid development of sensor technologies should bring the price down  
20 and make them more accessible to institutes, research groups, governments and personal users.

21 The validation work and the potential future work about the thermal camera have been  
22 discussed extensively in (20). The use of the thermal camera system for safety analysis at  
23 different locations and for different types of road users in nighttime conditions will be explored.  
24 The exposure used in this paper potentially provides a more precise measure to describe the  
25 pedestrian-vehicle interactions which, compared to exposure measures based on traffic volumes,  
26 are more closely related to pedestrian safety. A PET threshold of 20 seconds was set empirically  
27 to cover all potential conflicts, while the use of this threshold needs to be further explored and  
28 validated. Besides, the methodology and the safety measures used in this paper should be  
29 appropriate for the analysis of signalized intersections. However, the performance of thermal  
30 videos for safety analysis at busy intersections will be tested and the use of the safety measures  
31 should be further validated.

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37

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