Neural Network

November 9, 2021

1 Libraries

Import your libraries https://curiousily.com/posts/build-your-first-neural-network-with-pytorch/

```
[1]: import torch
  import os
  import numpy as np
  import pandas as pd
  from tqdm import tqdm
  import seaborn as sns
  from pylab import rcParams
  import matplotlib.pyplot as plt
  from matplotlib import rc
  from sklearn.utils import resample
  from sklearn.model_selection import train_test_split
  from sklearn.metrics import confusion_matrix, classification_report
  from torch import nn, optim
  import torch.nn.functional as F
```

[2]: !nvidia-smi

Tue Nov 9 14:31:26 2021

```
+----+
| NVIDIA-SMI 470.63.01 | Driver Version: 470.63.01 | CUDA Version: 11.4
l-----
| GPU Name Persistence-M| Bus-Id Disp.A | Volatile Uncorr. ECC |
| Fan Temp Perf Pwr:Usage/Cap| Memory-Usage | GPU-Util Compute M. | | MIG M. |
O NVIDIA GeForce ... Off | 00000000:05:00.0 Off |
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 1 NVIDIA GeForce ... Off | 00000000:09:00.0 Off |
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| 30% 27C P8 20W / 250W | 8560MiB / 11019MiB | 0% Default |
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```

30% 	26C	P8	3W / 29	50W 	7976MiB / 11019MiB	0% 	Default N/A
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2 Importing Data

Import the CSV file with Actions, Sum and Div as a Dataframe called df. Fill the empty values of Action with 0. Replace NaN values with 0. Delete first 100 rows.

```
[3]:
          Unnamed: 0
                       frAcc frRoAcc
                                        frDispl
                                                  frRoAng frSpeed
                                                                     timeLine
     99
                   99
                         0.0
                                             0.0
                                                       0.0
                                                                0.0
                                                                          1.00
                                   0.0
     100
                  100
                         0.0
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                                             0.0
                                                       0.0
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                                                                          1.01
     101
                  101
                         0.0
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                                             0.0
                                                       0.0
                                                                0.0
                                                                          1.02
                         0.0
     102
                  102
                                   0.0
                                             0.0
                                                       0.0
                                                                0.0
                                                                          1.03
```

```
103
             103
                    0.0
                              0.0
                                        0.0
                                                 0.0
                                                                     1.04
                                                           0.0
     frameRotationalSpeedX
                              frameRotationalSpeedY
                                                       frameRotationalSpeedZ
99
                         NaN
                                                  NaN
100
                         NaN
                                                  NaN
                                                                           NaN
101
                         NaN
                                                 NaN
                                                                          NaN
102
                         NaN
                                                 NaN
                                                                          NaN
103
                         NaN
                                                  NaN
                                                                           NaN
     wheelRotationalSpeedX
                              wheelRotationalSpeedY
                                                       wheelRotationalSpeedZ
99
                         NaN
                                                  NaN
                                                                           NaN
100
                         NaN
                                                 NaN
                                                                           NaN
101
                         NaN
                                                 NaN
                                                                          NaN
102
                         NaN
                                                  NaN
                                                                          NaN
103
                         NaN
                                                  NaN
                                                                           NaN
     frRoSpeed
                 Sum_WheelX_FrameZ
                                     Div_FrameZ_WheelX
                                                          Filt_WheelX \
99
           0.0
                                NaN
                                                     NaN
                                                                   0.0
100
           0.0
                                NaN
                                                     NaN
                                                                   0.0
101
           0.0
                                NaN
                                                     NaN
                                                                   0.0
102
           0.0
                                NaN
                                                     NaN
                                                                   0.0
103
           0.0
                                NaN
                                                     NaN
                                                                   0.0
     Filt_FrameZ Action
99
              0.0
                      NaN
              0.0
                      NaN
100
101
              0.0
                      NaN
102
              0.0
                      NaN
103
              0.0
                      NaN
```

3 Pre Preprocessing

```
[4]: cols = ['wheelRotationalSpeedX','frameRotationalSpeedY','frAcc','Action']

df = df[cols]

# Fill NaN with 0

df.replace([np.inf, -np.inf], np.nan, inplace=True)

df = df.fillna(0)

#Convert Sprinting to 1

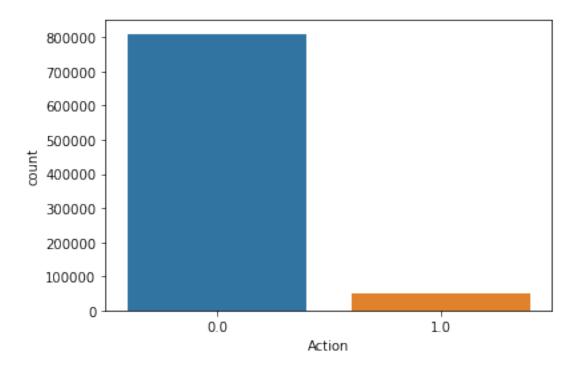
df.Action.replace({'Sprinting': 1},inplace=True)

sns.countplot(df['Action'])
```

/opt/jupyterhub/anaconda/lib/python3.9/site-packages/seaborn/_decorators.py:36: FutureWarning: Pass the following variable as a keyword arg: x. From version 0.12, the only valid positional argument will be `data`, and passing other arguments without an explicit keyword will result in an error or misinterpretation.

warnings.warn(

[4]: <AxesSubplot:xlabel='Action', ylabel='count'>

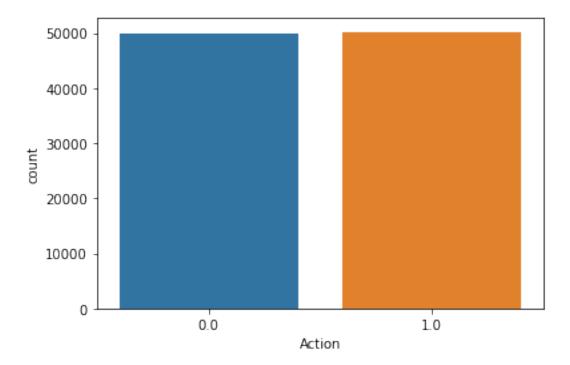


/opt/jupyterhub/anaconda/lib/python3.9/site-packages/seaborn/_decorators.py:36:

FutureWarning: Pass the following variable as a keyword arg: x. From version 0.12, the only valid positional argument will be `data`, and passing other arguments without an explicit keyword will result in an error or misinterpretation.

warnings.warn(

[5]: <AxesSubplot:xlabel='Action', ylabel='count'>



Convert the X_train, X_test, y_train, y_test to Tensors

```
[7]: X_train = torch.from_numpy(X_train.to_numpy()).float()
    y_train = torch.squeeze(torch.from_numpy(y_train.to_numpy()).float())
    X_test = torch.from_numpy(X_test.to_numpy()).float()
    y_test = torch.squeeze(torch.from_numpy(y_test.to_numpy()).float())
    print(X_train.shape, y_train.shape)
    print(X_test.shape, y_test.shape)
```

```
torch.Size([80152, 3]) torch.Size([80152])
torch.Size([20039, 3]) torch.Size([20039])
```

4 NN def

Define the Neural Network

```
[8]: class NN_model(nn.Module):
    def __init__(self, n_features):
        super(NN_model, self).__init__()
        self.fc1 = nn.Linear(n_features, first)
        self.fc2 = nn.Linear(first, second)
        self.fc3 = nn.Linear(second, 1)

    def forward(self, x):
        x = F.relu(self.fc1(x))
        x = F.relu(self.fc2(x))
        return torch.sigmoid(self.fc3(x))

first = 50
    second = 10

NN = NN_model(X_train.shape[1])
```

5 Training the NN on the GPU

```
[9]: criterion = nn.BCELoss()
    optimizer = optim.Adam(NN.parameters(), lr=0.001)

device = torch.device("cuda:0" if torch.cuda.is_available() else "cpu")
    X_train = X_train.to(device)
    y_train = y_train.to(device)
    X_test = X_test.to(device)
    y_test = y_test.to(device)
    NN = NN.to(device)
    criterion = criterion.to(device)
```

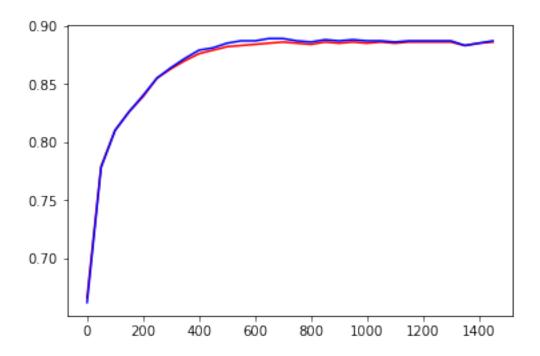
6 Define functions for calculating Accuracy of model

```
[10]: def calculate_accuracy(y_true, y_pred):
    predicted = y_pred.ge(.5).view(-1)
    return (y_true == predicted).sum().float() / len(y_true)
```

7 For loop through different epochs

```
[11]: def round_tensor(t, decimal_places=3):
        return round(t.item(), decimal_places)
      Results = pd.DataFrame(columns = ['Epoch', 'Acc_train', 'Acc_test'])
      for epoch in range(1500):
              y_pred = NN(X_train)
              y_pred = torch.squeeze(y_pred)
              train_loss = criterion(y_pred, y_train)
              if epoch % 50 == 0:
                  train_acc = calculate_accuracy(y_train, y_pred)
                  y_test_pred = NN(X_test)
                  y_test_pred = torch.squeeze(y_test_pred)
                  test_loss = criterion(y_test_pred, y_test)
                  test_acc = calculate_accuracy(y_test, y_test_pred)
                  result = {'Epoch': epoch, 'Acc_train': round_tensor(train_acc),_
       →'Acc_test': round_tensor(test_acc)}
                  Results = Results.append(result, ignore_index=True)
              #print(
      #f'''epoch {epoch}
      #Train set - loss: {round_tensor(train_loss)}, accuracy:
      \rightarrow {round_tensor(train_acc)}
      #Test set - loss: {round_tensor(test_loss)}, accuracy: {round_tensor(test_acc)}
      #''')
              optimizer.zero_grad()
              train_loss.backward()
              optimizer.step()
```

```
[12]: plt.plot(Results.Epoch,Results.Acc_train,'r',Results.Epoch,Results.Acc_test,'b') plt.show()
```



8 Validate/Tune Model

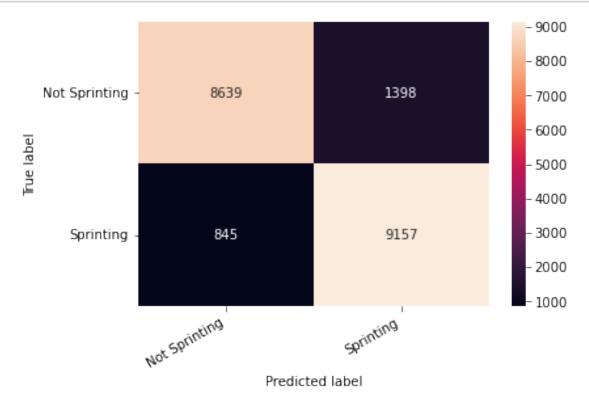
Validate results of the model (Precision/Recall). Tune the parameters of the model to achieve better results

```
[13]: classes = ['Not Sprinting', 'Sprinting']
y_pred = NN(X_test)
y_pred = y_pred.ge(.5).view(-1).cpu()
y_test = y_test.cpu()
print(classification_report(y_test, y_pred, target_names=classes))
```

```
precision
                             recall f1-score
                                                  support
                                          0.89
Not Sprinting
                     0.91
                                0.86
                                                    10037
    Sprinting
                                0.92
                                          0.89
                     0.87
                                                    10002
     accuracy
                                          0.89
                                                    20039
                     0.89
                                0.89
                                          0.89
                                                    20039
    macro avg
weighted avg
                     0.89
                                0.89
                                          0.89
                                                    20039
```

```
[14]: cm = confusion_matrix(y_test, y_pred)
df_cm = pd.DataFrame(cm, index=classes, columns=classes)
hmap = sns.heatmap(df_cm, annot=True, fmt="d")
```

```
hmap.yaxis.set_ticklabels(hmap.yaxis.get_ticklabels(), rotation=0, ha='right')
hmap.xaxis.set_ticklabels(hmap.xaxis.get_ticklabels(), rotation=30, ha='right')
plt.ylabel('True label')
plt.xlabel('Predicted label');
```



9 Saving Model

MODEL_PATH = 'model.pth' torch.save(NN, MODEL_PATH)

10 Restoring Model

 $NN = torch.load(MODEL_PATH)$