1D CNN Dataloader

December 7, 2021

1 Libraries

 $Import\ your\ libraries\ https://towards datascience.com/how-to-use-convolutional-neural-networks-for-time-series-classification-56b1b0a07a57$

```
[1]: import torch
     import os
     import math
     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 torch.utils.data import DataLoader, TensorDataset
     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
```

using gpu 3

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.

```
[2]: #load in df
Player = 15
Game = 2
Quarter = 4

#df = pd.read_csv('matrix_Player_' + str(Player) + '_game_' + str(Game) + \_
→ '_QuarterSplit.csv')
```

```
df = pd.read_csv('Split_RNN_player15game2.csv')
     df_y = pd.read_csv('Player_15_Game2_Sprints_Q1234.csv')
     df_y = df_y[['Action','Quarter','timeLine']]
     \#df_y = df_y.iloc[::2]
     df['wheelRotationalSpeedX_Diff'] = np.insert(np.diff(df.
     \hookrightarrowwheelRotationalSpeedX,n=1),0,0)
     df.head()
[2]:
        Unnamed: 0
                       frAcc frRoAcc frDispl frRoAng frSpeed timeLine \
                                2828.7
                                         3394.9
                                                  81.515 0.23278
                                                                      3581.0
     0
                 0
                   17.91200
     1
                 1
                     7.14760
                               2828.7
                                         3395.7
                                                  81.397 0.41190
                                                                      3581.0
     2
                 2
                   -0.89061
                                2828.8
                                         3396.5
                                                  82.233 0.48338
                                                                      3581.0
     3
                 3
                     4.17050
                                2828.8
                                         3397.3
                                                  74.342 0.47447
                                                                      3581.0
     4
                 4
                     1.15710
                                2828.8
                                         3398.0
                                                  74.332 0.51618
                                                                      3581.0
        frameRotationalSpeedX frameRotationalSpeedY frameRotationalSpeedZ
     0
                       7.3500
                                              -8.9367
                                                                       80.033
                                                                       80.010
     1
                       4.0600
                                              -8.1200
     2
                     -17.5700
                                              -0.4200
                                                                       81.340
     3
                      -1.6940
                                             -10.5000
                                                                       72.576
     4
                      -2.0922
                                              -6.1600
                                                                       73.111
        wheelRotationalSpeedX wheelRotationalSpeedY wheelRotationalSpeedZ
     0
                      -32.737
                                              -39.114
                                                                       45.033
                                                                       38.570
     1
                       -1.050
                                              -15.960
     2
                       10.780
                                              -32.340
                                                                       45.640
     3
                       16.485
                                              -41.601
                                                                       51.163
     4
                       23.847
                                              -34.619
                                                                       54.281
        frRoSpeed Filt_WheelX Filt_FrameZ Action
                                                       Quarter
     0
        -11.8030
                     67.674366
                                    8.849375
                                                 0.0
                                                             1
     1
          83.6110
                     65.140780
                                    8.214781
                                                 0.0
                                                             1
     2
      -789.0700
                     62.446959
                                    7.721630
                                                 0.0
                                                             1
     3
         -1.0099
                     59.592743
                                    7.380241
                                                 0.0
                                                             1
                     56.579696
                                    7.199759
          94.2010
                                                 0.0
                                                             1
        wheelRotationalSpeedX_Diff
     0
                              0.000
     1
                             31.687
     2
                             11.830
     3
                              5.705
     4
                              7.362
```

3 Pre Preprocessing

```
[3]: #Convert Sprinting to 1
df.Action.replace({'Sprinting': 1},inplace=True)
```

4 Data Preparating

Split data into a train and test set

```
[4]: train = df[df.Quarter != Quarter]
    test = df[df.Quarter == Quarter]

y_train = df_y[df_y.Quarter != Quarter]
y_test = df_y[df_y.Quarter == Quarter]
y_test = y_test.iloc[:-1 , :]

def rounddown(x):
    return (int(math.ceil(x / 100.0)) * 100) - 100

X_train = train[['wheelRotationalSpeedX','frameRotationalSpeedZ','frAcc']]
X_train = X_train.iloc[0:rounddown(len(X_train))]

y_train = y_train[['Action']]

X_test = test[['wheelRotationalSpeedX','frameRotationalSpeedZ','frAcc']]
X_test = X_test.iloc[0:rounddown(len(X_test))]

y_test = y_test[['Action']]
```

4.1 Slicing the train and test sets into windows of 1 sec (100 samples per window)

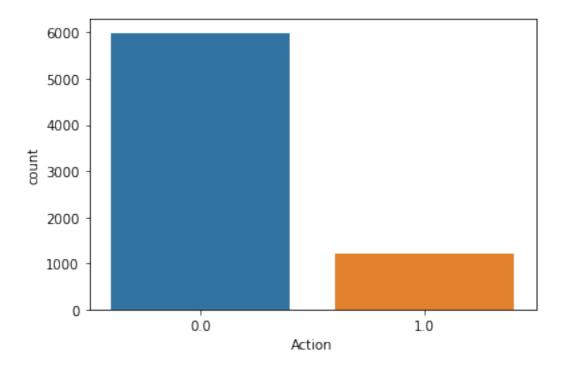
```
X_train = X_train.reshape([int(len(X_train)),channels,size_batch])
print(X_train.shape)
```

(7190, 3, 100)

/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(

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



4.2 Balancing the data (Copy all positives and paste them after X_train)

```
[8]: X_train_Resample = pd.DataFrame()
y_train_Resample = pd.DataFrame()

y_train = y_train.squeeze()
y_train = y_train.to_numpy()

print(y_train)

for i in range(0,len(y_train)):
    if y_train[i] == 1:
        X_train_Resample = X_train_Resample.append(pd.DataFrame(X_train[i]))
        y_train_Resample = y_train_Resample.append(pd.DataFrame([1]))
```

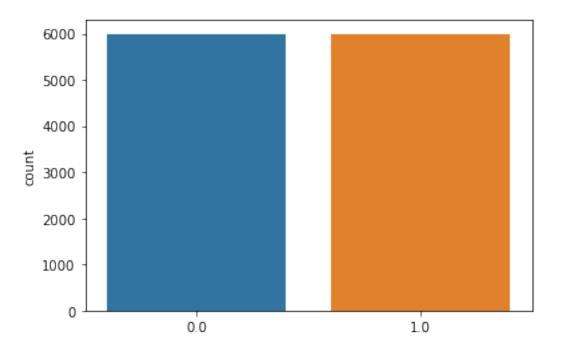
[0. 0. 0. ... 0. 0. 0.]

[1 1 1 ... 1 1 1]

/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(

[9]: <AxesSubplot:ylabel='count'>



4.3 Convert the X_train, X_test, y_train, y_test to Tensors

5 CNN def

Define the Convolutional Neural Network

```
[12]: class model(nn.Module):
    def __init__(self,n_features,kernel_size):
        super(model, self).__init__()
        #Use Padding to get good results
        self.conv1 = nn.Conv1d(n_features, 36, kernel_size=kernel_size, stride

→= 1, padding='same') #3 input channels, 18 output channels
```

```
self.conv2 = nn.Conv1d(36, 78, kernel_size=kernel_size, stride = 1,__
 →padding='same') #18 input channels from previous Conv. layer, 36 out
        self.conv2_drop = nn.Dropout2d() #dropout
        self.fc1 = nn.Linear(78, 54) #Fully-connected classifier layer
        self.fc2 = nn.Linear(54, 19) #Fully-connected classifier layer
        self.fc3 = nn.Linear(19,1) #Fully-connected classifier layer
   def forward(self, x):
        x = F.relu(F.max_pool1d(self.conv1(x), 10)) #Use bigger Pool1d for model
        x = F.relu(F.max_pool1d(self.conv2_drop(self.conv2(x)), 10))
        #point A
       x = x.transpose(1, 2)
        #point B
       x = self.fc1(x)
       x = F.relu(x)
       x = F.dropout(x, training=self.training)
       x = self.fc2(x)
       return torch.sigmoid(self.fc3(x))
   def post_forward(self, y):
       return torch.round(y)
CNN = model(X_train.shape[1],50)
```

6 Training options

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

7 Training the NN on the GPU

```
[14]: device = torch.device("cuda:0" if torch.cuda.is_available() else "cpu")

X_test = X_test.to(device)
y_test = y_test.to(device)

CNN = CNN.to(device)
criterion = criterion.to(device)
```

8 Define functions for calculating Accuracy of model

```
[15]: def calculate_accuracy(y_true, y_pred):
    return (y_true == y_pred).sum().float() / len(y_true)
```

9 For loop through different epochs

```
[16]: def round_tensor(t, decimal_places=3):
          return round(t.item(), decimal_places)
      Results_acc = pd.DataFrame(columns = ['Epoch', 'Acc_train', 'Acc_test'])
      Results_loss = pd.DataFrame(columns = ['Epoch', 'Loss_train', 'Loss_test'])
      Results recall = pd.DataFrame(columns = ['Epoch', 'Recall test'])
      Results_prec = pd.DataFrame(columns = ['Epoch', 'Prec_test'])
      for epoch in range(100):
          for x, y in train_dl:
              x, y = x.to(device), y.to(device)
              optimizer.zero_grad()
              y_pred = CNN(x)
              y_pred = y_pred.squeeze()
              train_loss = criterion(y_pred, y)
              train loss.backward()
              optimizer.step()
          if epoch % 1 == 0:
              train_acc = calculate_accuracy(y, CNN.post_forward(y_pred))
              train_loss = criterion(y_pred,y)
              y_test_pred = CNN(X_test)
              y_test_pred = torch.squeeze(y_test_pred)
              test_loss = criterion(y_test_pred, y_test)
              test_acc = calculate_accuracy(y_test, CNN.post_forward(y_test_pred))
              Confusion = confusion_matrix(y_test.cpu(),y_test_pred.ge(.5).view(-1).
       →cpu())
              test_recall = Confusion[1][1]/(Confusion[1][1] + Confusion[1][0])
              test_prec = Confusion[1][1]/(Confusion[0][1] + Confusion[1][1])
```

```
Acc = {'Epoch': epoch, 'Acc_train': round_tensor(train_acc), 'Acc_test':

round_tensor(test_acc)}

Loss = {'Epoch': epoch, 'Loss_train': round_tensor(train_loss),__

'Loss_test': round_tensor(test_loss)}

Recall = {'Epoch': epoch, 'Recall_test': round_tensor(test_recall)}

Prec = {'Epoch': epoch, 'Prec_test': round_tensor(test_prec)}

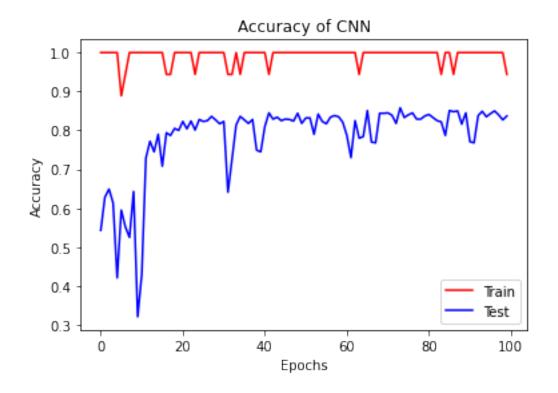
Results_acc = Results_acc.append(Acc, ignore_index=True)

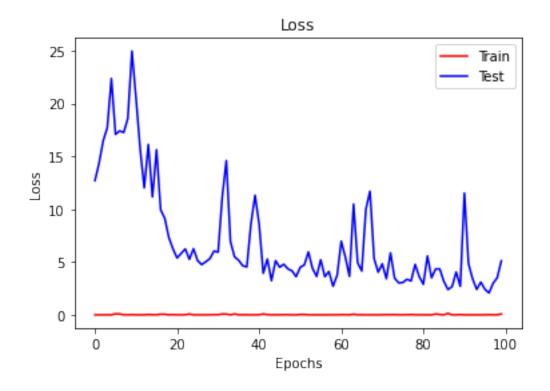
Results_loss = Results_loss.append(Loss, ignore_index=True)

Results_recall = Results_recall.append(Recall, ignore_index=True)

Results_prec = Results_prec.append(Prec, ignore_index=True)
```

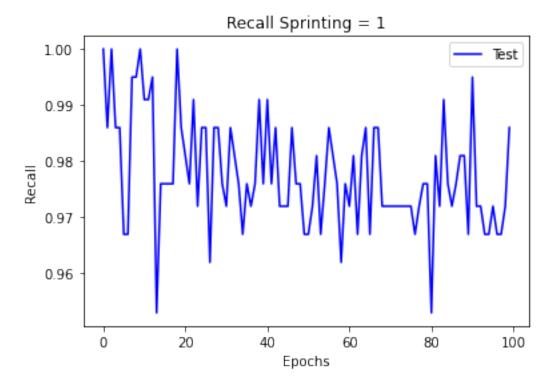
/opt/jupyterhub/anaconda/lib/python3.9/sitepackages/torch/nn/modules/conv.py:297: UserWarning: Using padding='same' with
even kernel lengths and odd dilation may require a zero-padded copy of the input
be created (Triggered internally at /opt/conda/condabld/pytorch_1634272068185/work/aten/src/ATen/native/Convolution.cpp:647.)
return F.conv1d(input, weight, bias, self.stride,

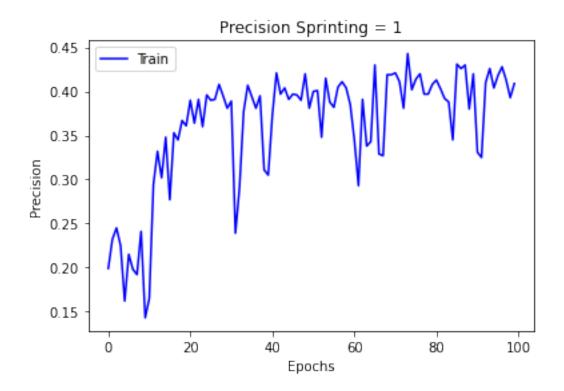




```
[18]: plt.plot(Results_recall.Epoch , Results_recall.Recall_test,'b')
   plt.legend(['Test'])
   plt.title('Recall Sprinting = 1')
   plt.ylabel('Recall')
   plt.xlabel('Epochs')
   plt.show()

plt.plot(Results_prec.Epoch,Results_prec.Prec_test,'b')
   plt.legend(['Train'])
   plt.title('Precision Sprinting = 1')
   plt.ylabel('Precision')
   plt.xlabel('Epochs')
   plt.show()
```





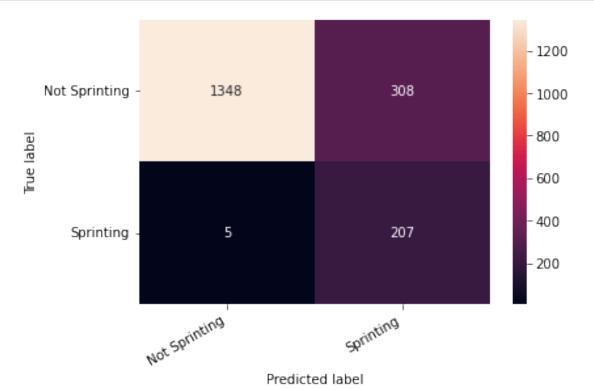
10 Validate/Tune Model

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

```
[19]: classes = ['Not Sprinting', 'Sprinting']
    y_pred = CNN(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
Not Cominting	1 00	0.01	0.00	1656
Not Sprinting	1.00	0.81	0.90	1656
Sprinting	0.40	0.98	0.57	212
accuracy			0.83	1868
macro avg	0.70	0.90	0.73	1868
weighted avg	0.93	0.83	0.86	1868

```
[20]: 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');
```



11 Closing Notebook

```
[]: %%javascript
Jupyter.notebook.session.delete();

<IPython.core.display.Javascript object>
[]:
```