## Chapter 3: Completed Work

### Methods

#### Subjects

Five adult males, ages 24–57, with normal or corrected-to-normal vision, participated in the experiments. All subjects participated in two fMRI sessions and a third session to acquire a high-resolution structural anatomy. Informed consent was obtained from all subjects under a protocol approved by the University of Texas at Austin Institutional Review Board.

#### Stimulus

For designing our virtual environment, we used the Unreal Developer's Kit developed by Epic Games, Inc.. This development kit is available free of charge for non-commercial applications (<http://www.unrealengine.com/udk>) and uses the same rendering and game engine found in many current and popular video games.

|  |  |  |
| --- | --- | --- |
| (a) | (b) | (c) |

Figure . The stimulus in the experiment described in this paper employs a virtual environment and a blocked design where the view alternates between moving through the environment and viewing groups of animated characters. (a) An example frame from the stimulus where the camera is traveling through the virtual environment with no characters presented. (b) An example frame from the stimulus where five friendly characters are being presented. (c) An example frame from the stimulus where three hostile characters are being presented. Such stimuli allow studying how the brain responds in a more natural and complex environment.

We created a virtual environment suggestive of a town in the Middle East (Figure 1). The stimulus was rendered in real-time from the point of view of a camera moving at eye level through the town, providing a first-person-perspective experience. Virtual characters representing friendly forces and hostile combatants were situated at four locations in the town. The camera would travel steadily on a predefined path from one part of the town to another over a 15 second interval during which no characters were visible. When one of the pre-determined locations was reached, characters would appear for 15 seconds during which the camera panned back-and-forth slowly while keeping all the characters in the field-of-view. The characters engaged in simple repetitive animated movement sequences. The number of characters presented at each of these locations varied from one to six, but the number and position of the characters did not vary over each 15-second period (Figure 1(b) and (c)). The 30-second block design of the stimulus was used for feature selection and for improving classifier performance (see below). The MVPA classification was always applied only to the periods of time when characters were presented. While the stimulus followed a 30-second block design, the subject always had the context of being present in the virtual town. This was done in order to preserve as much realism as possible by avoiding a discontinuity in context induced by using a blank screen for contrast.

A scanning session of a single subject entailed five to six “runs”, where each run was six minutes in duration. During a single run, every possible number of characters, from one to six, was presented twice, for a total of 12 presentations of characters (15 sec. each). The order of the number of characters was generated by a random permutation of 1–6 applied twice, once for the first half of the run and once for the second half. Since we placed characters at only four different locations in the town, the camera made 3 loops through the town in order to provide 12 presentations of characters. Finally, the type of character, soldiers or insurgents, was the same through a given run, and this character type was alternated between runs.

The subjects were not given any specific instructions other than to view the scene. The subjects were not military personnel, and they were not instructed to perceive specific characters as friendly or hostile. No background context was provided to bias the way the subjects perceived the environment.

Our VE stimulus was designed to reduce low-level visual differences between the group-number categories. First, the imagery was never static. Once again, achieving as much realism as possible motivated this decision. It is well known that the visual experience of looking at still-imagery is quite different from looking at moving imagery (Spiers & Maguire, 2007a). Second, the distance and viewpoint of the character groups was randomized from presentation-to-presentation to reduce low-level contrast differences between character-number categories. In addition, the subject performed free viewing of the scene, so exploratory eye movements should average away any local contrast correlations with character number. However, it is possible that the total contrast across the scene is correlated with character count, as this would not be affected by eye movements. Therefore, we calculated total scene contrast for each frame of the stimulus using the root-mean-square (RMS) contrast measure (Kukkonen, Rovamo, Tiippana, & Näsänen, 1993). We then fit a GLM to the result with character counts 0–6 as explanatory variables and performed a t-test on each of these variables to determine if a significant correlation existed between total scene contrast and character count (Friston et al., 1994). To determine what effect any such correlations, whether significant or not, had on the performance of the classifiers, we trained an SVM on the total contrast data and compared the performance with the fMRI data. Performance was estimated using 2-fold cross-validation. Since the total contrast is identical for each run there are only 2 possible folds that are unique and contain every character count.

#### MRI Protocols

Imaging was performed on a GE Signa Excite HD 3T scanner using the product eight-channel head coil. Whole-brain image volumes were collected using a custom GRAPPA EPI sequence (Griswold et al., 2002). Sequence parameters were g-factor = 2, TE = 25 ms, TR = 2.5 s, and 2.5-mm cubic voxels across a 200 mm field-of-view. The slice prescription included 40 slices oriented along the AC-PC axis. A high-order shim was performed before the start of the functional imaging to improve field homogeneity.

A set of T1-weighted structural images was obtained on the same prescription before the functional acquisition runs using a three-dimensional (3D) fast RF-spoiled gradient-echo (fSPGR) sequence. These anatomical images were then used to align the functional data to a structural 3D reference volume, which was acquired for each subject in a separate session. The structural reference volume was T1-weighted with good gray-white contrast and was acquired using a 3D inversion-prepared fSPGR sequence (minimum TE and TR, TI = 450 ms, 15° flip angle, isometric voxel size of 0.7 mm, 2 excitations, ~28-minute duration).

#### Preprocessing

Preprocessing of the fMRI data was performed using the mrVista software package (available at <http://vistalab.stanford.edu/>), modified for use in our own lab. The first 15 seconds of data were discarded to reduce transient effects. Within-scan motion was then estimated using a robust intensity-based scheme (Nestares & Heeger, 2000). Between-run motion was corrected using the same scheme, this time applied to the temporal average intensity of the entire scan. The first run of the session was used as the reference. Because the goal is to learn associations between patterns of activation in the brain and stimulus presentation, it is important that the activation is temporally aligned with the stimulus. Therefore, a Wiener filter deconvolution (Poor, 1980) was applied using a generic difference-of-gamma hemodynamic response function (Glover, 1999) as the kernel to the recorded BOLD signal. Mostly, the deconvolution served to shift the peak response in time so that it was aligned with its associated stimulus, but it also provided some amount of noise reduction. The high-resolution reference anatomies were segmented using the Freesurfer image analysis suite (http://surfer.nmr.mgh.harvard.edu/) to create approximate parcellations of the gray matter in each subject, as well as a surface model for visualization of mapping results.

#### Cross-Validation

The performance of machine learning algorithms is generally defined to be the expected accuracy of the classifier on previously unseen examples (Bishop, 2006). In practice, this measure can only be estimated. A typical approach is to split the available examples into training and test sets. The classifier is first trained on the training set, and its performance on the test set is then taken as the estimate of classifier performance on future unseen data. The splitting process is performed multiple times to reduce the variance of the performance estimate. This procedure is known as k-fold cross-validation (Kohavi, 1995).

In order to generate p values for these performance estimates, the null distribution for the cross-validated performance was generated by randomly permuting the labels on the examples 2000 times and repeating the training and cross-validation procedure. That is, the distribution of performance estimates was generated under the assumption that the labels and data were independent. Using this distribution, p values were calculated for the performance estimates (Ojala & Garriga, 2010). The high-performance computing resources of the Texas Advanced Computing Center at The University of Texas at Austin were utilized to perform this computation.

Previous studies (Pereira et al., 2009) have raised issues with performance estimates that are optimistically biased due to temporal correlations between examples (time frames) that violate standard assumptions of independence between training and test sets. For fMRI, the hemodynamic response introduces temporal correlations on the order of 10 seconds, which raises the question: What is the relationship between performance estimates and temporal correlation? To address this question, we estimated classifier performance when classifying number of characters presented using four different methods for splitting the data between training and test sets. Frames where no characters were present were removed, leaving 72 frames per run. We grouped different numbers of the remaining consecutive frames into selection units: 1 frame (frame split), 6 frames (block split), 36 frames (half-run split), and 72 frames (run split). For each of these unit sizes, we formed training and test sets by randomly selecting individual units (without replacement) and estimated classifier performance using these sets. For the frame and block splits, classifier performance was estimated using ten-fold cross-validation. For the half-run and run splits, only eight- and four-fold cross-validation was used respectively, due to the limited number of runs per subject. Based on our results, we chose to utilize the block split for performance estimates, as it did not exhibit an optimistic bias and allowed us to use more folds in the cross-validation procedure, which reduces the variance of the performance estimates.

#### Feature Selection

We used feature selection methods to remove uninformative voxels, thus improving both training time and performance of the machine-learning algorithms. This was particularly important for the NN, where training times can be quite long compared to the other methods. Common tools for feature selection in neuroimaging include anatomical region-of-interest (ROI) selection, principal component analysis (PCA; (Hotelling, 1933)), and univariate statistical tests. ROI selection is a powerful aide for hypothesis testing, but is much less useful for data exploration. PCA selects the orthogonal projections with the highest variance, which are generally dominated by physiological nuisance and is therefore not well suited for our purposes. Instead, we used ANOVA (Scheffe, 1959), which has been shown to be effective for feature selection in the context of MVPA (Norman, Polyn, Detre, & Haxby, 2006; Pereira et al., 2009). The idea behind ANOVA is to calculate the mean and variance for the set of samples in each class (e.g. number of characters), and then use these statistics to determine how different the distributions for each class are. We used ANOVA in one of two different ways: selecting voxels that differed significantly between with-character and without-character periods, or selecting voxels that differed significantly across classification targets (i.e. number of characters). To calculate significance, ANOVA estimates the probability that the means of two different samples are different. For comparison, we performed both task-activated feature selection and classification-target feature selection. We found classification-target feature selection yielded the best results on this dataset. Additionally, care must be taken to avoid optimistically biasing the accuracy estimates; voxel selection must be performed within each fold of a cross-validation procedure.

#### Classification

Using the time series from the voxels selected by the ANOVA process, we constructed classifiers of the following types: one-versus-one multi-class linear support-vector machine with C = 1 (Cortes & Vapnik, 1995; Weston & Watkins, 1999), feed-forward neural network with scaled conjugate gradient backpropagation training (Hagan & Menhaj, 1994; Hornik, Stinchcombe, & White, 1989; Møller, 1993), Gaussian naive Bayes classifier (GNB) (Duda & Hart, 1973), and k-nearest neighbor classifier (KNN) with k = 6 (Cover & Hart, 1967). The parameters for the SVM and KNN were determined by a grid-search (Hsu, Chang, & Lin, 2010) on a left-out dataset. That is, the parameters were obtained on data not used in the cross-validation procedure to estimate performance. The performance of each classifier was estimated for three different classification problems: whether characters were present, how many characters were present, and what type of characters was present. For the former classification, the full time series was utilized; for the latter two classifications, we used only the fMRI data obtained during the character-present periods. The number of examples for each label was always balanced.

Although the NN can potentially learn more complex classification functions than the other algorithms, it uses a stochastic training process and has many more free parameters. To overcome these issues, we performed model selection within each fold of the cross-validation procedure using a validation phase. First, part of the training data was held out as the validation set. We then performed a grid-search on the number of hidden nodes and selected the best value based on the network’s performance on the held-out validation set. Then, using this hidden-node value, we trained 20 more networks and again selected the best network based on performance on the held out validation set. This procedure reduced considerably the variance of the NNs cross-validated performance.

#### Classifier Probability and Confidence

All classifiers return a label for an input, but not all classifiers return the probability that the label is correct. For example, the SVM can only return a label, whereas the GNB classifier and feed-forward NN can return the probability for all labels (Richard & Lippmann, 1991). Normally, one chooses the label with the maximum probability as the selected class while ignoring its value, but we explored the use of this probability information to improve classification accuracy. It is also useful to consider a heuristic, which we shall call confidence, which is correlated with the probability that the chosen label is correct. For the GNB classifier, the probability of the chosen label can be used directly. However, the output of the NN is only an approximation of the posterior probabilities. Therefore, the outputs are first normalized to sum to one across all labels, and then the output corresponding to the selected label is taken to be that label’s confidence. Since the SVM only returns a label, generating a measure of confidence is not as straightforward and we therefore elected to only measure the confidence of the NN. How well confidence correlates with the true probability depends on how well the NN has approximated the joint probability distribution after training. The true probability cannot be measured directly, but we can compare the average confidence with the average probability that a label is correct, that is, the estimated classifier accuracy. To see how well the NN is estimating the joint probability distribution, we averaged confidence across all frames in a session and plotted it against the session’s cross-validated performance. It is also worth noting that confidence is calculated from the output of a trained NN and an input example, but not the associated label. This means that confidence could potentially be used as an independent quality estimate if the neural network was trained on an independent dataset.

#### Block Integration

A common approach to boost classification accuracy is to average across frames in a stimulus block ( e.g. Pereira et al., 2009). We compared the use of individual frames as examples to the use of examples created by averaging across 15-second blocks, and found that the block-averaged examples produced better classifier performance. Block averaging exploits our prior knowledge about the temporal structure of the stimulus, but it is not the only alternative.

We explored three other approaches for exploiting this knowledge: block voting, confidence voting, and output averaging. Block voting can be applied to any machine-learning algorithm. In block voting, the classifier was trained using individual frames as input examples, but the classification of a block was chosen as the majority classification of all frames in that block – each frame in the block “votes” on the block classification. The block voting procedure can be interpreted as a median filter on the output of a classifier trained on individual frames, where is the classification of the block and are the classifications of the individual frames in the block. Confidence voting requires an algorithm that returns a probability along with the label. Confidence voting was similar to block voting, but each frame’s vote was weighted by the probability of the chosen label on that frame, where is the set of all classes, is the weight or confidence associated with frame , and is the indicator function for class . Output averaging requires an algorithm that returns a probability for each output class such as a NN. In output averaging, the probability values from the neural network were summed across the block and the label was selected to be the class with the greatest value, where is the probability output of the neural network for class at frame .

#### Mapping

We have extended NN sensitivity analysis to determine the spatial distribution of voxels that contribute to the classification of each class. The key idea is calculate the sensitivity (or derivative) of the neural network output (classes) with respect to each input (voxels). Let be the vector of outputs and be the vector of inputs. Then the sensitivity of output to input is defined by , which is the partial derivative of the output with respect to the input. Let be the weight matrix from the hidden layer to the output layer and be a single element of corresponding to the weight on the network edge connecting output k with hidden node j. Similarly, let be the weight matrix from the input layer to the hidden layer and be a single edge weight. Then the partial derivative can be expressed as , where is the total number of hidden units in that layer of the neural network, is the value of the derivative of the activation function at output , and is the value of the derivative of the activation function at hidden neuron . Finally, the entire sensitivity matrix can be expressed in matrix notation as , where and .

Since the activation functions are generally non-linear, the sensitivity matrix becomes a function , where is an input vector. However, the sensitivity matrix for a particular input vector can vary due to the stochastic nature of training neural networks. To compensate for this added variance, we trained 100 different nets and calculated the average sensitivity matrix across these samples.

We now have a sensitivity score for each voxel at all time points and for all output classes. However, we would like a measure of sensitivity only on voxels. Therefore, we calculated for each point in the time series, and then computed the RMS average sensitivity matrix across all input vectors as , where is the number of input vectors (time points). gives a sensitivity value for each voxel with respect to all outputs. We then calculated the maximum sensitivity of each voxel across all outputs, i.e. . This sensitivity was projected back into the volume anatomy to create a map of the relative incremental importance of each voxel's response to the classification decision.

In order to empirically determine a sensitivity threshold to eliminate irrelevant voxels, we propose an approach based on recursive feature elimination (RFE; (Guyon et al., 2002)) adapted to the feed-forward neural network. A similar approach was used by (Formisano, De Martino, & Valente, 2008) in conjunction with the weight vector of a regularized SVM. In RFE, a machine-learning algorithm is first trained on a full data set. Next, some ranking criterion is calculated for each input dimension. The dimension with the lowest rank is removed from the dataset (a fixed number or percentile of dimensions may be removed for speed reasons). Then, the machine-learning algorithm is retrained on the reduced dataset. This process can be repeated until all features have been removed. The performance of each subset can be calculated using a held-out test set to determine a good threshold to remove irrelevant voxels. We used the feed-forward neural network as our machine-learning algorithm, and the measure for our ranking criterion. For computational speed reasons as well as for inter-subject comparison, we used a fixed sensitivity threshold at each iteration to determine which features would be removed. This allowed us to bootstrap classifier performance on a held-out test set across all sessions to obtain 68% confidence intervals (Efron, 1979).

For a qualitative comparison, we created surface maps for the NN sensitivity analysis, GLM, and searchlight. These techniques cannot be used for a direct quantitative comparison because they present fundamentally different information. Similarly, the thresholds used for each map are not directly comparable. However, the thresholds have been selected based on standard practices for determining meaningful localization of function and information. For sensitivity analysis, recursive feature elimination was performed on each subject's volume sensitivity map until the bootstrapped classier performance fell significantly below (p = 0.05) the peak classifier performance. The resulting maps were projected onto their cortical surfaces and blurred along the surface using a 5 mm full-width half-maximum (FWHM) Gaussian kernel (voxel size is 2.5 mm). For GLM, a linear activation model was constructed using an explanatory variable for each character count. Processing of fMRI data was carried out using FEAT (FMRI Expert Analysis Tool) Version 5.98, part of FSL. Z (Gaussianized T/F) statistic images were thresholded using clusters determined by Z>2.3 and a (corrected) cluster significant threshold of P=0.05 (Worsley, 2001). For searchlight, we employed a 3x3x3 kernel and a linear SVM classifier using the PyMVPA toolkit (Hanke et al., 2009). The searchlight maps were thresholded at twice chance decoding accuracy (33%). These maps were then projected onto the Freesurfer generated surfaces for each subject. We attempted to use non-linear warping to create a group average, but we were not satisfied with the registration accuracy. In particular, there was a tendency to confuse activity on superior temporal areas with that on dorsal parietal regions. To average across subjects, therefore, we aggregated the maps across ten anatomical labels automatically generated by Freesurfer during surface construction. To account for variations in the total surface area covered by the different maps, we calculated percent coverage, the fractional area of the thresholded map contained within each surface label, and bootstrapping was used to calculate 68% confidence intervals for all three approaches and all ten surface labels.

### Results

#### Classification Accuracy

We built classifiers for three separate cases: with/without characters, 1—6 characters, and soldiers vs. insurgents. Recall that the with/without characters case has a block structure of 15 sec. for each condition, and that both conditions contained images of the town. For this case, classification performance was excellent, with typical scores of 94%-97% for the NN. This high performance was not too surprising, as there were strong low-level visual image differences between these two conditions. In contrast, the third case of distinguishing between soldiers and insurgents did not produce classification performance well above chance. Consequently, we focused our analysis on the second case, character counting where we did not distinguish between soldiers and insurgents.

We tested the cross-validated performance of the classifiers on four different training-and-test split methods to determine the method that would yield unbiased performance estimates with the lowest variance (Figure 2). Our results indicate that block split was the best method for estimating performance and subsequent results used this procedure.



Figure . The estimated performance of the classifiers averaged across all sessions and plotted across the four training-and-test-split methods; error bars show bootstrapped 68% confidence intervals. There is a statistically significant drop in the estimated performance when the average minimum temporal delay increases from 2.6 to 21 seconds, though performance stays above the chance performance of 16.7%. This result confirms that short delays result in optimistic performance estimates because of temporal correlations.

To ensure that total contrast was not a confounding element in our results, we built a GLM with the total frame contrast as the target and the number of characters as explanatory variables. The resulting p values for this model are presented in the following table.

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| Character Count | 1 | 2 | 3 | 4 | 5 | 6 |
| p value | 0.027 | 0.717 | 0.002 | 0.156 | 0.166 | 0.884 |

We found that character counts 1 and 3 did have a statistically significant correlation with total contrast. We also calculated the Pearson correlation coefficient between total contrast and character count while leaving out the 0 character blocks (r = 0.1598) and its significance (p = 0.1800), which did not show significant correlation. However, statistically significant trends do not necessarily drive high classifier performance, though they can contribute. To determine how much this affect could have contributed to classifier performance, we trained an SVM on only the total contrast information and measured its performance with cross-validation. We found the performance on only total contrast to be 25% and approximately 66% of the correct guesses were for character count 1 and 3. Therefore, the total contrast likely did impact classifier performance, but only for character counts 1 and 3. Furthermore, this cross-validated performance is significantly lower than the performance achieved by our machine learning algorithms on the fMRI data.

Averaged across all 10 sessions (five subjects with two sessions each), the cross-validated performance estimates of all four classifiers are significantly above chance, where chance is 1 out of 6 = 16.7% (Figure 3). The SVM had the best performance, followed by the feed-forward NN (without using our new output processing techniques; see below). The performance of all four independent classifiers being above chance increases confidence in the results, however the GNB and KNN classifiers will not be discussed further as their performance was significantly below the SVM and NN. There is considerable variation in performance between sessions for the same subject, as well as variation in average performance between subjects.



Figure . The estimated performance of all four classifiers averaged across all sessions. The performance of individual sessions are indicated by the symbols. Each subject performed two sessions and there are therefore two symbols per subject. The performances estimates were bootstrapped across sessions in order to obtain 68% confidence intervals. While the SVM had the best average performance, all four classifiers performed well above a chance performance of 16.7%.

It is also worth noting the computation time of these algorithms in practice. The average training time was 0.683 ms per example for the SVM, 121.299 ms per example for the NN, 0.073 ms per example for the GNB, and 0.044 ms per example for the KNN. The training time of the NN is this ~2 orders of magnitude slower than the SVM. Nevertheless, the full NN cross validation procedure still only took approximately 10 minutes per session. The average decoding time was 0.431 ms per example for the SVM, 0.197 ms per example for the NN, 0.172 ms per example for the GNB, and 0.466 ms per example for the KNN. Unlike training times, the NN is the second fastest at decoding.

We tested four different methods for exploiting the block structure of the stimulus to improve classification accuracy: input averaging, block vote, confidence vote, and output averaging. Since confidence vote and output averaging require an estimate for the probability of each output label, only the feed-forward NN was considered for this comparison. Both block voting methods, and output averaging improved session performance significantly over simple input averaging. The output averaging method had the greatest average improvement (Figure 4).

|  |  |
| --- | --- |
|  |  |

Figure . The chart on the left shows individual session accuracies for all four averaging methods. The sessions have been sorted by average performance for improved readability. The chance probability for all sessions is 16.7%. The chart on the right shows the impact of the individual aggregation methods calculated relative to the baseline score as 10 log(score/baseline) for each session. These relative accuracy scores (in dB) are averaged across all sessions and bootstrapped to obtain 68% confidence intervals.

mri:Neurometrics:manuscript:confidence-confusion.pdf

Figure . The average confusion matrices for the feed-forward NN with output averaging across all subjects. The value in cell (i,j) of the matrix is the percent of examples from class i that were labeled as class j; values along the diagonal indicate correctly classified examples while the rest indicate incorrectly classified examples. The color of the cell indicates deviation from chance probability (16.7%); greener cells indicating values above chance, and redder cells indicating values below chance.

It is clear from Figure 4 that not all sessions performed equally well. Even for the same subject, session performance varied significantly. We found that the average confidence (i.e., the probability of the chosen label) returned by the NN was very significantly correlated (R2 = 0.98; negligible p) with the network’s cross-validated performance (Figure 6). The confidence measure was calculated without knowledge of the labels and thus provides a measure of the quality of the data being classified as well as an estimate for how well the NN has estimated the joint probability distribution.



Figure . Cross-validated session accuracy plotted against average session confidence.

From the confusion matrix in Figure 5, we see that the classifier is best at detecting the presence of a single character. In fact, there are relatively few cases of confusion between one and two characters. Apparently, these two situations evoke very different responses in the brain. Also, note that the majority of the incorrect responses lay just off the main diagonal. These responses correspond to the classifier being wrong by a single character in its classification. 1 and 3 characters were classified with the highest accuracy. This is likely due in part to the correlation with total scene contrast. However, note that 2 characters were also classified with high accuracy and yet had the second lowest p value for contrast correlation.

#### Mapping

Sensitivity maps for individual subjects show a preponderance of classification sensitivity in lateral occipital areas, ventral early visual areas, and dorsal parietal lobe (Figure 7). Subjects also displayed small regions of high sensitivity in portions of temporal and frontal cortex. There is significant overlap between the sensitivity, GLM, and searchlight maps, but the sensitivity maps show greater contributions from anterior brain regions.



Figure . A qualitative comparison of sensitivity, GLM linear-response Z-statistic, and searchlight accuracy maps projected onto semi-inflated cortical surfaces for three different subjects. The maps are roughly similar across subjects and hemispheres, but substantial individual variations are evident.

The information contained in these maps are not equivalent, and neither are their associated thresholds. The thresholds were chosen based on accepted practice for their associated technique, but they are not statistically equivalent and should only be used for qualitative comparison. Sensitivity threshold values were determined using a recursive feature elimination approach (section 0). GLM linear-response Z-statistic maps and searchlight accuracy maps are also presented for comparison. The sensitivity maps were thresholded using the recursive feature elimination technique described in the methods. The Z statistic images were thresholded using clusters determined by Z > 2.3 and a (corrected) cluster significant threshold of P=0.05 (Worsely 2001). The searchlight maps are thresholded at twice chance probability (33%). Figure 8 presents the performance of the NN and the fraction of voxels remaining after each iteration. Greater than half the voxels can be removed without significant loss of classification performance.



Figure . A plot of the feedforward neural network estimated performance and the fraction of voxels remaining at each iteration of the recursive feature elimination procedure. The fraction of voxels is calculated with respect to the 2000 voxels selected by ANOVA. The performance estimates and voxel counts were bootstrapped across sessions in order to obtain 68% confidence intervals.

We calculated percent coverage for each of the three mapping methods on Freesurfer anatomical surface labels (section 0). Results were averaged across all sessions and bootstrapped to obtain 68% confidence intervals (Figure 9). These numbers agree with our observations on the individual surface maps; there is substantial overlap between all three maps in lateral occipital and lingual cortex. Elsewhere the mapping methods show different patterns of response. For example, early visual cortex, roughly demarcated by the pericalcarine and cuneus labels, shows greatest classification sensitivity by the searchlight technique, intermediate response based on GLM, and relatively low information content based on our NN sensitivity metric. Interestingly, several temporal lobe regions show greater sensitivity based on the NN metric than either of the others. To determine if the sensitivity in these regions is meaningful, we estimated the performance of the NN on a subset of the original voxels constructed by taking all of the voxels considered significant by the sensitivity analysis and removing all those voxels considered significant by GLM. The cross-validated performance on this subset averaged across all sessions was 25% (with p < 0.05 for all sessions). While the performance dropped substantially, these voxels were still able to classify character count significantly above chance.



Figure . A bar graph depicting the coverage percent from the sensitivity, GLM, and searchlight maps across automatically generated labels from Freesurfer. The coverage percent is the percent of the map contained within that area. In this way, the variation in total map size between approaches is controlled for and specificity and coverage of the maps can be directly compared. Coverage percentages were bootstrapped across sessions to provide confidence intervals.

### Discussion

We set out with the practical goal of decoding the subject’s cognitive state associated with viewing a number of characters from time series of functional images. Using a combination of standard and novel machine-learning methods, we were able to extract this information with accuracy that varied from well above chance to nearly perfect (Figure 4), depending upon session and machine-learning algorithm. For the neural network results, we then presented a novel approach to relating the network’s decision-making sensitivity back to brain anatomy of the individual. These sensitivity maps suggest that a more widespread and diverse network of brain regions encoded the cognitive state, which is consistent with the complex nature of the VE stimulus.

The work described in this paper expands the opportunities for utilizing virtual environments for scientific inquiry in cognitive neuroscience. The design of the stimulus provided a balance between realism and experimental control so that quantitative analysis of the fMRI data stream achieved a degree of confidence ranging from satisfactory (well above chance) to very high. Care was taken to preserve as much of a natural experience as possible. For example, we never exposed the subject to disruptions in the experience of being present in a virtual environment, yet the stimulus had an otherwise classic block design. And the synthesized video stream never showed static images at any time, which rarely occur under natural conditions. We also eschewed averaging data between different subjects in accordance with one of our goals: modeling individuals for therapies and learning regimens, including utilizing real-time fMRI.

Despite these seemingly greater challenges, we were able to achieve classifier performance that was significantly above chance with all four of the MVPA methods we tested. More importantly, for the two strongest methods, support-vector machines and artificial neural networks, the classifier performance was sometimes good enough to enable practical applications. This is especially impressive given that the cognitive states being discriminated were not based on differing object categories (e.g. houses, faces, tools, etc.) that often activate brain regions with limited anatomical overlap (Hanson, Matsuka, & Haxby, 2004), but rather were from a single object category, viz. combatants, and differed only in number of combatants.

We also discovered that the performance of classic feed-forward neural networks (NN), which have been somewhat neglected lately in favor of SVM, can be competitive with SVM on the data in this study. While the inherent properties of SVM make it well suited to sparse representations (small number of object categories vs. large number of voxels), neural networks provide a more general method that can (in principle) capture more subtle features given enough data. Moreover, NNs provide probability values that can be used to further improve classification performance. Looking to the future, building NNs using “deep learning” (Hinton, Osindero, & Teh, 2006b) has been shown repeatedly to outperform SVM on many types of data (Cireşan et al., 2012). Even greater classifier accuracy may be possible with such methods applied to VE data.

Classifier performance will be important for both on-line use of fMRI in brain-computer interfaces (BCI), such as PTSD therapy, as well as for off-line creation of brain maps using sensitivity analysis. The techniques block voting, confidence voting, and output averaging (see section 2.9), all improved performance over the baseline classifier performance as well as over input averaging. The concept of using the output of the classifier to ascribe confidence (see section 2.8) to each output could be very useful for differentiating the reliability of entire sessions. Similarly, any confidence measure could be quite valuable in BCI applications in which low confidence frames could be weighted by confidence to reduce their influence and/or dropped entirely from any on-line decision-making by the BCI software.

Classification sensitivity in early retinotopic visual areas and lateral-occipital areas suggests that retinotopic organization is important to decoding group size for our VE stimulus. Because LO combines object-selectivity with retinotopic specificity (Sayres & Grill-Spector, 2008), different group sizes could evoke complex but stereotypical patterns of responses in LO (and other retinotopically organized areas) as subjects visually interrogate the stimuli with a sequence of eye movements. Regions in the parietal cortex have been shown to be involved in mental arithmetic and magnitude judgment (Rickard et al., 2000) which may also play some role in decoding group size. More recent research suggests this region may even contain a topographic representation of numerosity (Harvey, Klein, Petridou, & Dumoulin, 2013). There is some debate as to whether this topographic map represents numerosity or sensory processing (Gebuis, Gevers, & Cohen Kadosh, 2013), but it would be useful for decoding group size regardless.

Integrating information from the whole brain improves decoding accuracy, but it makes interpreting functional localization problematic. From our sensitivity analysis, we see that regions associated with low-level vision, higher-level object-recognition, and potentially even cognitive representations of numerosity all contributed to decoding. However, the sensitivity analysis does not necessarily tell us how these regions contributed. Eye movements and other behavioral responses as the subjects visually interrogate the stimuli could induce reliable and complex patterns of activation in all of these areas. For example, our control analysis indicates that low-level contrast features may have partially, but not entirely contributed to decoding. Similarly, increased eye movements could create a higher variance of activation in retinotopic visual areas. If this behavior is reliable and consistent, the machine learning algorithms will learn to use that information to help decode the state. At this early stage, we did not collect eye tracking data during our experiments to evaluate to what extent this contributed to decoding. Eye-movement information is not obviously correlated with character count, but rather the cognitive evoked in the subject by the VE: being in a town and freely viewing a specific number of characters. It is this VE-specific state that we are interested in decoding. Such goal-driven decoding should be more useful for training and therapy exercises where the underlying neural mechanisms may not yet be well understood. However, neuroscientific studies looking to leverage VEs and sensitivity mapping for functional localization must still be careful to balance realism with control to avoid these kinds of confounds when interpreting their results.

The GLM produced Z-statistic maps indicate significant activation only in early ventral visual areas and lateral occipital regions. Searchlight produced results qualitatively similar to GLM, suggesting that the expansion from a single voxel with GLM to a 3x3x3 set of voxels in searchlight was not sufficient to capture potentially important long-range multi-voxel response patterns identified by the NN sensitivity analysis. Therefore, we conclude that extracting response patterns by performing classification on voxels selected from a spatially diverse collection of voxels captures potentially important brain information missed by both GLM and searchlight (Figure 9).

Note that the information contained in the maps is quite different, making them difficult to compare directly. The Z-statistic maps tell us how well individual voxels agree with a hypothetical model, the searchlight maps tells us how well small localized groups of voxels are able to decode the desired brain state, and the sensitivity maps tells us how much individual voxels contribute to a spatially-distributed decoding decision. We do not have a practical way to calculate p-values for individual voxels with the sensitivity analysis so care must be taken when interpreting the results. However, a qualitative comparison of the techniques is still useful. While we are unable to calculate the significance of individual voxels for our sensitivity analysis, the comparison shows that the resulting sensitivity maps highlight regions consistent with accepted mapping techniques where per voxel significance calculations are possible. This increases our confidence that the areas indicated by the sensitivity analysis, but not the other techniques, likely do contain information relevant for decoding the subject’s brain state and could merit further investigation.

In conclusion, it is possible to extract useful information from fMRI data obtained using a realistic virtual environment stimulus using machine-learning methods. Neural networks, supplemented by some averaging techniques, performed particularly well. The resulting classification data, moreover, can be mapped onto the brain using a novel form of sensitivity analysis. These methods open up new possibilities for the use of virtual environments in both neuroscience research and in clinical applications.

### Methods

#### Stimulus

|  |  |
| --- | --- |
| (a) | (b) |

Figure . Example frames from the stimulus during task (a) and rest (b) phases.

We built a new stimulus from the ground up using the Unity game engine (<http://unity3d.com>) in order to improve both the realism of the virtual environment and the degree of control over presentation. New high-resolution models and textures were used to greatly improve the visual quality of the environment over the previous iteration. Additionally, characters were given improved animations and programmed with basic artificial intelligence to increase the realism of the environment. Given our long-term interest in PTSD, the virtual environment is intended to reflect real-world environments encountered by our military personnel. It is similar to the virtual Iraq used in recent virtual reality exposure therapy experiments to treat PTSD (Gerardi, Rothbaum, Ressler, Heekin, & Rizzo, 2008).

The stimulus alternated between task periods and rest periods, which lasted for 30 seconds each. During the rest period, the subject’s perspective moved along fixed paths through the virtual town (Figure 10b). During the task period, the subject’s perspective was stationary, but a large group of characters randomly milled around the scene while avoiding collisions with each other (Figure 10a).

The subject was tasked with identifying when a character draws a firearm. Periodically (every 2–6 s), one of the characters milling around the scene was selected at random to draw a firearm and then holster it after a fixed period of time. The subject was instructed to press a button whenever he identified a target character with a drawn firearm. A correct response was recorded if the subject pressed the button during the presentation period and an incorrect response was recorded if the subject failed to press the button before the firearm was holstered or the subject pressed the button when no character had drawn a firearm. A correct button press caused the target character to immediately holster their weapon, providing feedback to the subject.

Difficulty of the task was be controlled by adjusting the type of firearm the characters drew (pistol, rifle, or rocket-propelled grenade launcher), the distance of the character from the subject’s perspective, and the duration that the firearm was presented for. Extensive subject response data and target visibility information was written out to an XML file during game play which allowed us to determine the relationship between these parameters and the subject’s probability of success. We found a considerable amount of variability in the subject’s performance was explained by what we call total visibility: the visible area of the object to be detected in pixels integrated in time across the duration of its presentation (with the resulting units being pixel-seconds). Therefore, we calculated total visibility in real time to adjust the presentation period of the firearm. This allowed us to compensate for the variance introduced by partial and total occlusion of the firearm caused by the randomly moving characters. To create a single difficulty control, we held the type of firearm constant and linked total visibility to presentation distance, i.e., for a difficult trial, the character would be presented further away and with a smaller total visibility.

We collected fMRI data using 3 different variants of the task. In the first variant, difficulty was held constant during each 30-second block and the subject received a cue indicating the difficulty of that block before it started. Difficulty was only controlled by distance and the firearm presentation period was fixed. In the second variant, difficulty varied continuously during the block and no cue was presented. Difficulty was controlled using both distance and total visibility to adjust the presentation period. In the third variant, difficulty was held constant during each block and the subject was cued. Difficulty was controlled using both distance and total visibility to adjust the presentation period.

The task and difficulty parameters were designed to limit the correlation between low-level visual cues and task difficulty. Although the distance of the character selected to draw a firearm varied with difficulty, the average distance, density, and speed of the characters remained the same in all difficulty settings. The character with the firearm moved and behaved exactly like the other characters. The only difference between the difficulty settings is the size and location of the firearm itself, which has a very small size and contrast compared to the entire scene.

#### MRI

MRI data was collected on a Siemens Skyra 3T scanner. Compared to our previous work, this scanner allowed us to collect higher resolution data over a larger area of the brain without overheating; we could also collect more runs per session (see below). Four subjects participated in the experiments after giving informed consent under a human-subjects protocol approved by the UT Austin IRB.

#### Anatomy

High-resolution anatomy scans were collected for each subject. Automatic cortical segmentation and surface extraction was performed on these volumes using the Freesurfer image analysis suite, which is documented and freely available online (<http://surfer.nmr.mgh.harvard.edu>).

#### Functional

Functional data was collected using the Siemens product EPI sequence with grappa acceleration factor 3, 2 mm isometric voxels, 60 slices, and TR = 2.5 s. The prescription covered the whole brain and was oriented along the AC-PC axis. During each acquisition session, 8 runs were collected. Each run consisted of 8 alternations between 30-second task and rest periods for a total length of 6 minutes and 144 volumes. Motion correction and slice timing correction was performed using mrVista, which is documented and freely available online (<http://white.stanford.edu/software>).

#### Resting State

Resting state data was collected using similar acquisition parameters. During each session, six 6-minute duration runs were collected. Motion correction and slice timing correction were again performed using mrVista.

ICA extraction was performed using the MELODIC tool from the FSL analysis suite (<http://fsl.fmrib.ox.ac.uk>). MELODIC was configured to extract 70 components based on the findings of Ray et al. (2013). The resulting independent components were analyzed by hand to determine whether they appeared to be physiological noise, motion artifacts, or ICNs. Those identified as ICNs were also given semantic labels as outlined in Laird et al. (2011).

#### Machine Learning

Task difficulty was estimated for each frame using the target distance and total visibility information recorded during fMRI data acquisition along with the subject’s psychophysics curve. This continuous measure of task difficulty was then binned into 3 groups of equal size, i.e., each bin contained the same number of frames rather than being equal in width. We refer to these groups as easy, medium, and hard frames. These are the target classes which our machine learning algorithms were trained to classify.

We explored classifying these targets using whole-brain data as well as single ICNs. For single ICNs, masks were calculated by MELODIC and applied to the data before further processing. We selected 5 ICNs related to bottom-up attention and vision. We also selected 2 masks associated with physiological noise and motion artifacts as a sanity check.

Task relevant voxels were selected using an ANOVA approach (Scheffe, 1959). A single factor ANOVA analysis was performed independently on each voxel with the factor being whether the sample was recorded during a rest period or a task period. Voxels were then sorted based on their resulting F-test score and the first 3,000 voxels were selected for whole-brain data and the first 1,000 voxels were selected for ICNs. This served to reduce the dimensionality of the learning problem and thereby improve both training time and classifier performance.

The time series from these task relevant voxels and their associated difficulty targets were used to train a variety of machine learning algorithms. We found that the feed forward neural network (NN; Jain & Mohiuddin, 1996) had the best performance in this domain closely followed by the support vector machine (SVM; Cortes & Vapnik, 1995). Based on these findings, we will primarily focus on the results from the NN. Classifier accuracy was estimated using cross-validation (Kohavi, 1995). In our previous work we found that splitting the folds across the runs greatly reduced the bias of the performance estimate and therefore we used 8-fold cross-validation. P-values were estimated using a permutation test (Ojala & Garriga, 2010).

Sensitivity maps were constructed for each subject from neural networks trained on the whole-brain data and for each ICN (see our previous report; paper in preparation). These sensitivity maps were projected onto the Freesurfer generated cortical surfaces for visualization.

### Results

#### Psychophysics

The aggregate psychophysics plots for each subject are presented in Figure 11. These measurements include total visibility correction. Confidence intervals were calculated using the Clopper-Pearson method for binomial random variables (Clopper & Pearson, 1934). Although some variability is present between subjects and within difficulty settings, all of the curves have a significant downward trend as the difficulty increases.

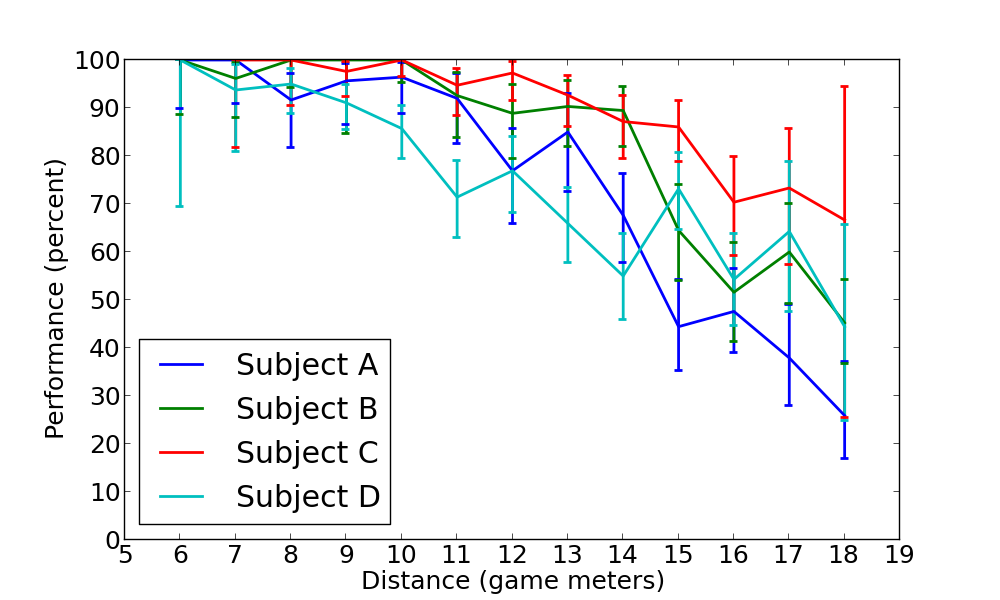


Figure . Aggregate psychophysics plots for each subject. These measurements include total visibility correction.

#### Machine Learning

Individual cross-validated accuracy for the NN and SVM using task-relevant feature selection on whole-brain data is presented in Table 1. The average classification accuracy across all subjects and stimulus variants is 48%. The performance of all subjects is significantly above chance (p < 0.05).

Table . Individual cross-validated accuracy for the NN across all 3 stimulus variants.

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| Stimulus Variant | Cued, no visibility control | | Non-cued, visibility control | | Cued, visibility control | |
| Subject | A | D | A | B | C | D |
| NN | 51%\* | 51%\* | 47%\* | 43%\* | 50%\* | 47%\* |
| SVM | 47%\* | 52%\* | 44%\* | 40%\* | 38%\* | 41%\* |

Sensitivity maps from whole-brain data are presented in Figure 12. These maps show high levels of sensitivity in the temporoparietal junction (TPJ) and lower levels of sensitivity in visual areas and premotor cortex.

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
|  | Left Lateral | Left Medial | Right Lateral | Right Medial |
| Subject A |  |  |  |  |
| Subject B |  |  |  |  |
| Subject C |  |  |  |  |
| Subject D |  |  |  |  |

Figure . Sensitivity maps from whole-brain data for each subject. The sensitivity maps have been projected onto the cortical surface.

So far, the ICN analysis has only been completed for subject C. The ICN masks used in this analysis are presented in Figure 13. ICN 4 corresponds to the bottom-up attention network; ICNs 5, 8, 10, and 21 correspond to different vision networks; ICN 7 corresponds to physiological noise; and ICN 11 corresponds to motion artifacts. The preliminary classification results from the analysis are presented in Table 2. Only ICNs 4 and 10—corresponding to the bottom-up attention network and one of the vision networks—had cross-validated accuracies significantly (p<0.05) above chance.

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| ICN | Left Lateral | Left Medial | Right Lateral | Right Medial |
| 4 |  |  |  |  |
| 5 |  |  |  |  |
| 7 |  |  |  |  |
| 8 |  |  |  |  |
| 10 |  |  |  |  |
| 11 |  |  |  |  |
| 21 |  |  |  |  |

Figure . Masks used in ICN analysis projected onto cortical surface.

Table . Cross-validated accuracy estimates for each ICN.

|  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- |
|  | Subject C | | | | | | |
| ICN | 4 | 5 | 7 | 8 | 10 | 11 | 21 |
| NN | 43%\* | 35% | 36% | 36% | 40%\* | 35% | 37% |

The sensitivity maps for ICN 4 and 10 are presented in Figure 14. [Note areas highlighted, also need to double check figures since they look reversed.]

|  |  |  |  |  |
| --- | --- | --- | --- | --- |
| ICN | Left Lateral | Left Medial | Right Lateral | Right Medial |
| 4 |  |  |  |  |
| 10 |  |  |  |  |

Figure . Sensitivity maps for ICNs 4 and 10, corresponding to the bottom-up attention network and posterior visual network respectively. These were the only ICNs of those selected for analysis that had a cross-validated classification accuracy significantly above chance (p<0.05).

### Discussion and Ongoing Work

The performance results are promising and show that decoding an internal mental variable while a subject performs a task in a realistic virtual environment is feasible. Although the performance is lower than when we were decoding visual information, the results are far more interesting. Additionally, we expect to be able to improve the results by further polishing the stimulus and applying more advanced machine learning techniques.

In addition to controlling the visibility of the target, we are modifying the stimulus to better localize task-relevant activation for improved classification performance. Currently, we select voxels for further processing based on a single-factor ANOVA test between task and rest periods. However, there are significant visual differences in the stimulus between these two periods as well. To solve this problem, we are restructuring the stimulus to minimize visual differences between these periods. Additionally, we are experimenting with reducing the duration of the rest period to maximize the number of useful frames we collect each session.

We have preliminary evidence that suggests that combining classification outputs from each frame in a block to produce a single classification for the block significantly increases performance. The first combination scheme we tried was a simple voting mechanism, but we are exploring other more complex methods as well. We are also experimenting with training hierarchical SVMs and NNs on the ICN subsets as well as anatomic percellations. The hierarchy should help the machine learning algorithms exploit these inherent structures in the data. Due to their complexity, we are building a new computational framework to efficiently train and test these networks. We are also exploring the use of classification confidence measures. This is a machine learning topic that has received little attention, but may be very important in the training and therapy domain. Frequently when a machine learning algorithm misclassifies an input, it is because that input is either ambiguous or unlike any example the classifier was trained on. It would be helpful to have the classifier report some measure of confidence, particularly in the case of real-time feedback where the subject can be guided back to a state where the classifier is more reliable. Additionally, the trainer or therapist could ask the subject to self report only when the classifier reports low confidence. These data samples could then be used to retrain an even better classifier. We are performing a thorough investigation of the reliability of different confidence measures on a variety different machine learning algorithms to determine their effectiveness.

We are currently in the process of identifying additional internal cognitive variables to target. We are planning experiments where we encourage the subject to use different high-level strategies for completing tasks. In this way we would be measuring distinct neural states rather than single cognitive variables. We expect to see the different strategies reflected in the spatial distributions shown by the sensitivity maps and the ICNs contributing to classification. Another potential target is the subjective units of distress scale (SUDS). In the work of Gerardi, Rothbaum, Ressler, Heekin, & Rizzo (2008), the patient undergoing the virtual reality expose therapy is asked to report his current level of distress in SUDS every 10 seconds. Providing this same measure to the therapist based on patterns of neural activation without having to interrupt the immersion of the procedure would be extremely helpful. Although there are additional complications associated with measuring distress and anxiety, our results thus far indicate that such a system is within the realm of possibility.

### Methods

#### Hidden Markov Model

To accurately model the state transition probabilities we found that we needed to use a discrete number of previous states. The set of brain states we are interested in decoding is , where for our stimulus. The domain of the hidden states is , where is the number of memory states we use. This results in an extremely large but sparse state transition matrix . The domain of the observable sequence is where is the number of voxels we are measuring. We use a trained feed-forward neural network to approximate from the observed fMRI data (Richard and Lippmann (1991)). We can’t generate an observation probability matrix because our observable domain is continuous, but by fitting a distribution to we can calculate using Bayes’ rule. Fortunately, prior fMRI studies have shown that the distribution of fMRI data can be reasonably approximated by a multivariate Gaussian after whitening (Worsley (2001)).

#### Modified Forward Algorithm

Based on this model, we propose the following modified forward algorithm for fMRI data. Given observations , a probability transition matrix , an observation probability distribution , a function that approximates , an initial state distribution , and , the filtered distribution for the state can be determined using Algorithm 4. The performance of this algorithm was estimated using a cross-validation procedure (Kohavi (1995)) because the distribution and the function need to be constructed on a training set. We compared it’s performance to simple block averaging on previously collected fMRI data.

**Algorithm 4** Forward Algorithm

#### Stimulus

The stimulus is a realistic virtual environment that the subject views while inside the scanner. The subject’s view movies through a virtual town and periodically stops while some number of human characters move onto the screen. The characters stay on the screen for 15 seconds before the view moves on. The subject is not instructed to perform any task and simply views the scene passively.

#### Subjects

Data was collected on 5 male subjects aged 25 to 57. For each subject, 2 sessions were collected.

#### State Space

The information we attempted to decode from the fMRI data was the number of characters visible on the screen. During the stimulus, the number of characters presented varied from 1 to 6 so we have 6 hidden states. However, we also considered the 5 previous states in our model which led to a total state space of 66 states. The observable was the fMRI data which was the BOLD signal on a 80 x 80 x 40 grid of voxels sampled every 2.5 seconds. Each 2.5 second period is called a frame and after removing the periods of moving through town we are left with 288 frames for each session.

#### Baseline

For baseline comparison, a neural network was trained to estimate the number of characters presented in each frame. We measured the decoding accuracy of the network, or the percent of correctly estimated states. The estimated state is taken to be the state with the maximum posterior probability. The accuracy of the classifier was estimated using cross-validation to avoid any bias.

#### Block Averaging

We also performed simple block averaging for comparison. During each 15 second period that characters are presented, the number of characters does not change. Therefore, we can average the fMRI data across these 15 second blocks to provide a better measurement. A second neural network was trained to estimate the number of characters presented in each block from the time- averaged fMRI data. The performance of the classifier was estimated using cross-validation.

#### Modified Forward Algorithm

The probability transition matrix was constructed such that the state would stay the same for 6 frames and then switch to another state with equal probability. Here, we are utilizing our knowledge that the number of characters stays the same for 15 seconds. This results in an extremely sparse transition matrix which we implemented using a sparse matrix class instead of forming a functional mapping. We estimated as a multivariate Gaussian which we fit to the fMRI data using a least squares approach. Similarly, we estimated using a trained neural network exactly as we did for the baseline. The modified forward algorithm was then used to generate the distribution for each frame. The state with the maximum posterior probability was selected as the estimated state for that frame. The accuracy of the model was estimated using cross-validation where both the training of the neural network and the estimation of the multivariate Gaussian were performed within each fold.

### Results

|  |  |
| --- | --- |
|  |  |

Figure 16. The results of the modified forward algorithm and basic block av- eraging on decoding presented character count from fMRI data in 10 different sessions. Results are reported in accuracy which is the percent of correctly decoded frames. Sessions are ordered by their baseline accuracy for easier read- ability and are not indicative of any kind of temporal trend. There is a significant variation in baseline performance which can be attributed to a variety of factors from scanner temperature to subject attentiveness. Therefore, to highlight the effect of the modified algorithm we also present relative accuracy (in dB) for ba- sic block averaging and the modified forward algorithm averaged across frames. Error bars represent 68% confidence intervals produced by bootstrapping.

### Conclusion

The results show that our modified forward algorithm is highly effective on an admittedly limited problem because the stimulus was still constructed using a rigid block structure. However, we believe these results show that the algorithm could be used to achieve good decoding performance even on a stimulus without a block structure. This opens the door for more naturally constructed stimuli which are important for therapy and training applications of fMRI. It should also be possible to construct modified forward-backward and Viterbi algorithms which could further improve decoding performance.