Machine Learning for prediction of Human Activity

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Introduction

Using devices such as Jawbone Up, Nike FuelBand, and Fitbit it is now possible to collect a large amount of data about personal activity relatively inexpensively. These type of devices are part of the quantified self movement â a group of enthusiasts who take measurements about themselves regularly to improve their health, to find patterns in their behavior, or because they are tech geeks. One thing that people regularly do is quantify how much of a particular activity they do, but they rarely quantify how well they do it. In this project, your goal will be to use data from accelerometers on the belt, forearm, arm, and dumbell of 6 participants. They were asked to perform barbell lifts correctly and incorrectly in 5 different ways. More information is available from the website here: http://web.archive.org/web/20161224072740/http:/groupware.les.inf.puc-rio.br/har (see the section on the Weight Lifting Exercise Dataset).

Get Data

Data for this assignment comes from Groupare@LES Project for Human Activity Recognition. There are 2 CSV files - one with training data and second with testing data.

> In this project, your goal will be to use data from accelerometers on the belt, forearm, arm, and dumbell of 6 participants. We load the data first.

```
training <- read.csv("pml-training.csv")
testing <- read.csv("pml-testing.csv")
str(training)
```

```
## 'data.frame':    19622 obs. of  160 variables:
##  $ X                       : int  1 2 3 4 5 6 7 8 9 10 ...
##  $ user_name               : Factor w/ 6 levels "adelmo","carlitos",..: 2 2 2 2 2 2 2 2 2 2 ...
##  $ raw_timestamp_part_1    : int  1323084231 1323084231 1323084231 1323084232 1323084232 1323084232 13230
84232 1323084232 1323084232 1323084232 ...
##  $ raw_timestamp_part_2    : int  788290 808298 820366 120339 196328 304277 368296 440390 484323 484434
...
##  $ cvtd_timestamp          : Factor w/ 20 levels "02/12/2011 13:32",..: 9 9 9 9 9 9 9 9 9 9 ...
##  $ new_window              : Factor w/ 2 levels "no","yes": 1 1 1 1 1 1 1 1 1 1 ...
##  $ num_window              : int  11 11 11 12 12 12 12 12 12 12 ...
##  $ roll_belt               : num  1.41 1.41 1.42 1.48 1.48 1.45 1.42 1.42 1.43 1.45 ...
##  $ pitch_belt              : num  8.07 8.07 8.07 8.05 8.07 8.06 8.09 8.13 8.16 8.17 ...
##  $ yaw_belt                : num  -94.4 -94.4 -94.4 -94.4 -94.4 -94.4 -94.4 -94.4 -94.4 -94.4 ...
##  $ total_accel_belt        : int  3 3 3 3 3 3 3 3 3 3 ...
##  $ kurtosis_roll_belt      : Factor w/ 397 levels "","-0.016850",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ kurtosis_picth_belt     : Factor w/ 317 levels "","-0.021887",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ kurtosis_yaw_belt       : Factor w/ 2 levels "","#DIV/0!": 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_roll_belt      : Factor w/ 395 levels "","-0.003095",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_roll_belt.1    : Factor w/ 338 levels "","-0.005928",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_yaw_belt       : Factor w/ 2 levels "","#DIV/0!": 1 1 1 1 1 1 1 1 1 1 ...
##  $ max_roll_belt           : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ max_picth_belt          : int  NA NA NA NA NA NA NA NA NA NA ...
##  $ max_yaw_belt            : Factor w/ 68 levels "","-0.1","-0.2",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ min_roll_belt           : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ min_pitch_belt          : int  NA NA NA NA NA NA NA NA NA NA ...
##  $ min_yaw_belt            : Factor w/ 68 levels "","-0.1","-0.2",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ amplitude_roll_belt     : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ amplitude_pitch_belt    : int  NA NA NA NA NA NA NA NA NA NA ...
##  $ amplitude_yaw_belt      : Factor w/ 4 levels "","#DIV/0!","0.00",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ var_total_accel_belt    : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ avg_roll_belt           : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ stddev_roll_belt        : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ var_roll_belt           : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ avg_pitch_belt          : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ stddev_pitch_belt       : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ var_pitch_belt          : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ avg_yaw_belt            : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ stddev_yaw_belt         : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ var_yaw_belt            : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ gyros_belt_x            : num  0 0.02 0 0.02 0.02 0.02 0.02 0.02 0.02 0.03 ...
##  $ gyros_belt_y            : num  0 0 0 0 0.02 0 0 0 0 0 ...
##  $ gyros_belt_z            : num  -0.02 -0.02 -0.02 -0.03 -0.02 -0.02 -0.02 -0.02 -0.02 0 ...
```

```
##  $ accel_belt_x           : int  -21 -22 -20 -22 -21 -21 -22 -22 -20 -21 ...
##  $ accel_belt_y           : int  4 4 5 3 2 4 3 4 2 4 ...
##  $ accel_belt_z           : int  22 22 23 21 24 21 21 21 24 22 ...
##  $ magnet_belt_x          : int  -3 -7 -2 -6 -6 0 -4 -2 1 -3 ...
##  $ magnet_belt_y          : int  599 608 600 604 600 603 599 603 602 609 ...
##  $ magnet_belt_z          : int  -313 -311 -305 -310 -302 -312 -311 -313 -312 -308 ...
##  $ roll_arm               : num  -128 -128 -128 -128 -128 -128 -128 -128 -128 -128 ...
##  $ pitch_arm              : num  22.5 22.5 22.5 22.1 22.1 22 21.9 21.8 21.7 21.6 ...
##  $ yaw_arm                : num  -161 -161 -161 -161 -161 -161 -161 -161 -161 -161 ...
##  $ total_accel_arm        : int  34 34 34 34 34 34 34 34 34 34 ...
##  $ var_accel_arm          : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ avg_roll_arm           : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ stddev_roll_arm        : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ var_roll_arm           : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ avg_pitch_arm          : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ stddev_pitch_arm       : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ var_pitch_arm          : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ avg_yaw_arm            : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ stddev_yaw_arm         : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ var_yaw_arm            : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ gyros_arm_x            : num  0 0.02 0.02 0.02 0 0.02 0 0.02 0.02 0.02 ...
##  $ gyros_arm_y            : num  0 -0.02 -0.02 -0.03 -0.03 -0.03 -0.03 -0.02 -0.03 -0.03 ...
##  $ gyros_arm_z            : num  -0.02 -0.02 -0.02 0.02 0 0 0 0 -0.02 -0.02 ...
##  $ accel_arm_x            : int  -288 -290 -289 -289 -289 -289 -289 -289 -288 -288 ...
##  $ accel_arm_y            : int  109 110 110 111 111 111 111 111 109 110 ...
##  $ accel_arm_z            : int  -123 -125 -126 -123 -123 -122 -125 -124 -122 -124 ...
##  $ magnet_arm_x           : int  -368 -369 -368 -372 -374 -369 -373 -372 -369 -376 ...
##  $ magnet_arm_y           : int  337 337 344 344 337 342 336 338 341 334 ...
##  $ magnet_arm_z           : int  516 513 513 512 506 513 509 510 518 516 ...
##  $ kurtosis_roll_arm      : Factor w/ 330 levels "","-0.02438",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ kurtosis_picth_arm     : Factor w/ 328 levels "","-0.00484",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ kurtosis_yaw_arm       : Factor w/ 395 levels "","-0.01548",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_roll_arm      : Factor w/ 331 levels "","-0.00051",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_pitch_arm     : Factor w/ 328 levels "","-0.00184",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_yaw_arm       : Factor w/ 395 levels "","-0.00311",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ max_roll_arm           : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ max_picth_arm          : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ max_yaw_arm            : int  NA NA NA NA NA NA NA NA NA NA ...
##  $ min_roll_arm           : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ min_pitch_arm          : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ min_yaw_arm            : int  NA NA NA NA NA NA NA NA NA NA ...
##  $ amplitude_roll_arm     : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ amplitude_pitch_arm    : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ amplitude_yaw_arm      : int  NA NA NA NA NA NA NA NA NA NA ...
##  $ roll_dumbbell          : num  13.1 13.1 12.9 13.4 13.4 ...
##  $ pitch_dumbbell         : num  -70.5 -70.6 -70.3 -70.4 -70.4 ...
##  $ yaw_dumbbell           : num  -84.9 -84.7 -85.1 -84.9 -84.9 ...
##  $ kurtosis_roll_dumbbell : Factor w/ 398 levels "","-0.0035","-0.0073",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ kurtosis_picth_dumbbell: Factor w/ 401 levels "","-0.0163","-0.0233",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ kurtosis_yaw_dumbbell  : Factor w/ 2 levels "","#DIV/0!": 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_roll_dumbbell : Factor w/ 401 levels "","-0.0082","-0.0096",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_pitch_dumbbell: Factor w/ 402 levels "","-0.0053","-0.0084",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ skewness_yaw_dumbbell  : Factor w/ 2 levels "","#DIV/0!": 1 1 1 1 1 1 1 1 1 1 ...
##  $ max_roll_dumbbell      : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ max_picth_dumbbell     : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ max_yaw_dumbbell       : Factor w/ 73 levels "","-0.1","-0.2",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ min_roll_dumbbell      : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ min_pitch_dumbbell     : num  NA NA NA NA NA NA NA NA NA NA ...
##  $ min_yaw_dumbbell       : Factor w/ 73 levels "","-0.1","-0.2",..: 1 1 1 1 1 1 1 1 1 1 ...
##  $ amplitude_roll_dumbbell : num  NA NA NA NA NA NA NA NA NA NA ...
##   [list output truncated]
```

Goal

The goal of your project is to predict the manner in which they did the exercise. This is the “classe” variable in the training set. You may use any of the other variables to predict with. You should create a report describing how you built your model, how you used cross validation, what you think the expected out of sample error is, and why you made the choices you did. You will also use your prediction model to predict 20 different test cases.

```
levels(training$user_name)
```

```
## [1] "adelmo"   "carlitos" "charles"  "eurico"   "jeremy"   "pedro"
```

```
levels(training$classe)
```

```
## [1] "A" "B" "C" "D" "E"
```

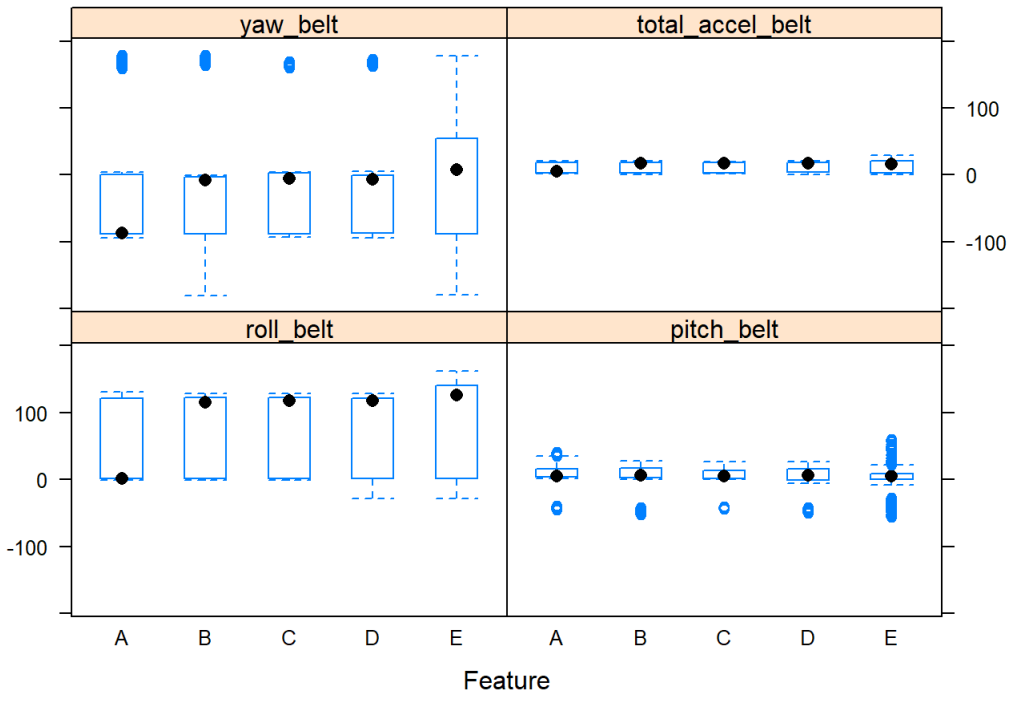
Cleaning Data

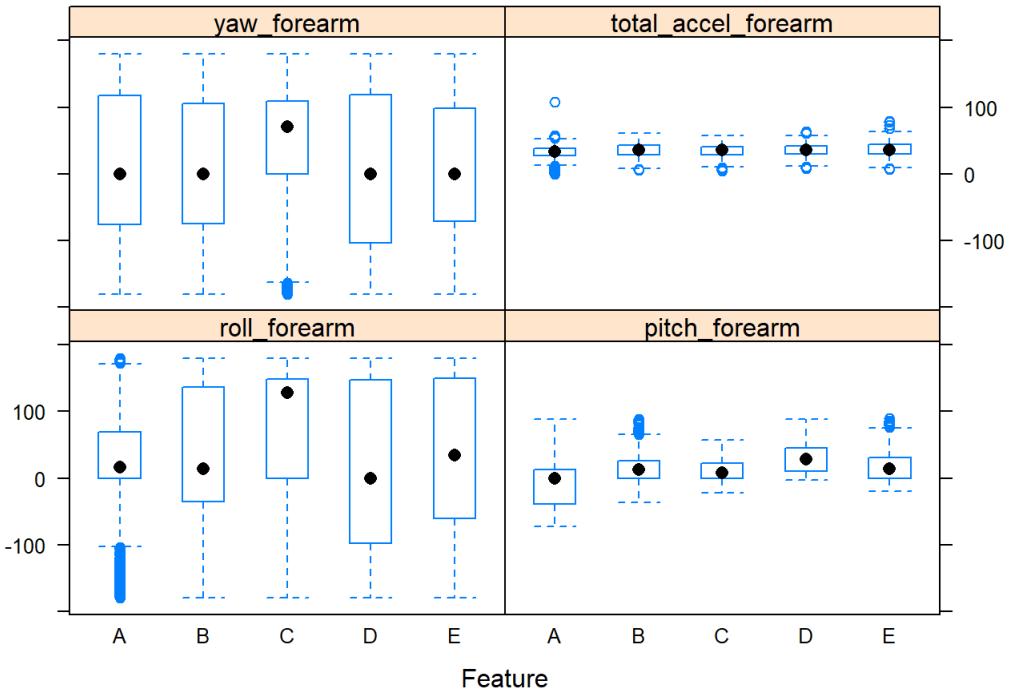
We will first remove the data containing the missing i.e. NA values

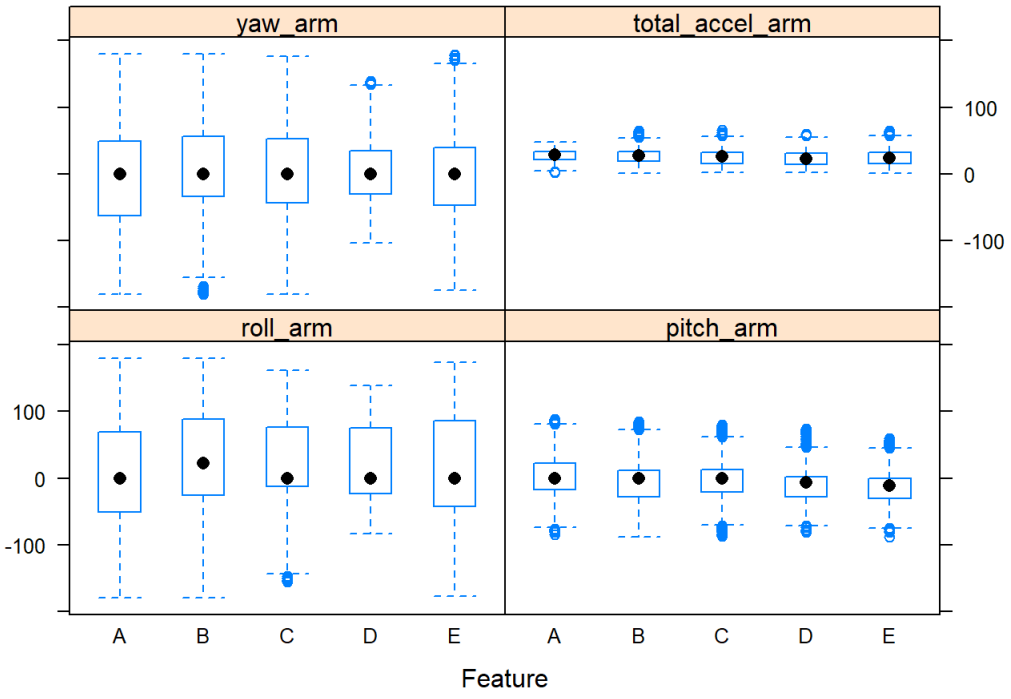
```
training <- read.csv("pml-training.csv", na.strings=c("NA","#DIV/0!", ""))
training <- training[, colSums(is.na(training)) == 0]
testing <- read.csv("pml-testing.csv", na.strings=c("NA","#DIV/0!", ""))
testing <- testing[, colSums(is.na(testing)) == 0]
names(training)
```

```
##  [1] "X"                    "user_name"            "raw_timestamp_part_1"
##  [4] "raw_timestamp_part_2" "cvtd_timestamp"       "new_window"
##  [7] "num_window"           "roll_belt"            "pitch_belt"
## [10] "yaw_belt"             "total_accel_belt"     "gyros_belt_x"
## [13] "gyros_belt_y"         "gyros_belt_z"         "accel_belt_x"
## [16] "accel_belt_y"         "accel_belt_z"         "magnet_belt_x"
## [19] "magnet_belt_y"        "magnet_belt_z"        "roll_arm"
## [22] "pitch_arm"            "yaw_arm"              "total_accel_arm"
## [25] "gyros_arm_x"          "gyros_arm_y"          "gyros_arm_z"
## [28] "accel_arm_x"          "accel_arm_y"          "accel_arm_z"
## [31] "magnet_arm_x"         "magnet_arm_y"         "magnet_arm_z"
## [34] "roll_dumbbell"        "pitch_dumbbell"       "yaw_dumbbell"
## [37] "total_accel_dumbbell" "gyros_dumbbell_x"     "gyros_dumbbell_y"
## [40] "gyros_dumbbell_z"     "accel_dumbbell_x"     "accel_dumbbell_y"
## [43] "accel_dumbbell_z"     "magnet_dumbbell_x"    "magnet_dumbbell_y"
## [46] "magnet_dumbbell_z"    "roll_forearm"         "pitch_forearm"
## [49] "yaw_forearm"          "total_accel_forearm"  "gyros_forearm_x"
## [52] "gyros_forearm_y"      "gyros_forearm_z"      "accel_forearm_x"
## [55] "accel_forearm_y"      "accel_forearm_z"      "magnet_forearm_x"
## [58] "magnet_forearm_y"     "magnet_forearm_z"     "classe"
```

Now, the exploratory analysis part to understand movements of different body parts with different exercises.







Prediction Model

We will use random forest model. Applying it on the belt.

```
modBelt_rf <- train(classe ~ roll_belt + pitch_belt + yaw_belt, method = "rf", data = training, ntree = 20)
```

```
## note: only 2 unique complexity parameters in default grid. Truncating the grid to 2 .
```

```
predBelt_rf <- predict(modBelt_rf, training)
sum(training$classe == predBelt_rf) / length(predBelt_rf)
```

```
## [1] 0.9859342
```

Now applying it on the forearm.

```
modForearm_rf <- train(classe ~ roll_forearm + pitch_forearm + yaw_forearm, method = "rf", data = training,
ntree = 20)
```

```
## note: only 2 unique complexity parameters in default grid. Truncating the grid to 2 .
```

```
predForearm_rf <- predict(modForearm_rf, training)
sum(training$classe == predForearm_rf) / length(predForearm_rf)
```

```
## [1] 0.8583223
```

The belt result was satisfactory, the forearm result not so much because of the expectation of primary movement in curl.Not so good, mainly because one would expect the forearm to be the primary movement in the curl. Movement in other less-involved parts of body increases the error.

Applying on the arm:

```
modArm_rf <- train(classe ~ roll_arm + pitch_arm + yaw_arm, method = "rf", data = training, ntree = 20)
```

```
## note: only 2 unique complexity parameters in default grid. Truncating the grid to 2 .
```

```
predArm_rf <- predict(modArm_rf, training)
sum(training$classe == predArm_rf) / length(predArm_rf)
```

```
## [1] 0.8840077
```

Other modelling methods trial gave lower accuracy.

Testing

Prediction model applied to testing dataset.

```
predBeltTest <- predict(modBelt_rf, testing)
predForearmTest <- predict(modForearm_rf, testing)
predArmTest <- predict(modArm_rf, testing)
table(predBeltTest, predForearmTest, predArmTest)
```

```
## , , predArmTest = A
##
##             predForearmTest
## predBeltTest A B C D E
##            A 5 1 1 0 0
##            B 0 1 0 0 0
##            C 0 0 0 0 0
##            D 1 0 0 1 0
##            E 0 0 1 0 1
##
## , , predArmTest = B
##
##             predForearmTest
## predBeltTest A B C D E
##            A 0 0 0 0 0
##            B 0 4 0 1 0
##            C 0 0 0 0 0
##            D 0 0 0 0 0
##            E 0 0 0 0 1
##
## , , predArmTest = C
##
##             predForearmTest
## predBeltTest A B C D E
##            A 1 0 0 0 0
##            B 0 0 0 0 0
##            C 0 0 0 0 0
##            D 0 0 0 0 0
##            E 0 0 0 0 0
##
## , , predArmTest = D
##
##             predForearmTest
## predBeltTest A B C D E
##            A 0 0 0 0 0
##            B 0 0 0 0 0
##            C 0 0 0 0 0
##            D 0 0 0 0 0
##            E 0 0 0 0 0
##
## , , predArmTest = E
##
##             predForearmTest
## predBeltTest A B C D E
##            A 0 0 0 0 0
##            B 0 0 0 0 1
##            C 0 0 0 0 0
##            D 0 0 0 0 0
##            E 0 0 0 0 0
```