## Title Page:

Comparing Spatial Transformers and Random Forest for EEG-Based 3D Object Manipulation in Brain-Computer Interfaces

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**Keywords:** Spatial Transformers, Random Forest , EEG Signals, 3D Object Manipulation, Brain-Computer Interfaces (BCIs)

# ABSTRACT

# Aim: This research aims to compare the performance of Spatial Transformers and Random Forests (RFs) in processing generalized electroencephalogram (EEG) signals for 3D object manipulation within Brain-Computer Interfaces (BCIs), focusing on differentiating and integrating EEG signals to enable hand movement adaptation in virtual 3D environments. Materials and Methods: A sample size of n = 10 was used for both Spatial Transformers and Random Forest, with statistical power set at 80%, a significance threshold of 0.05%, and a 95% confidence interval for mean and standard deviation. The implementation utilized a simulated EEG dataset tailored for 3D object manipulation tasks. Conclusion: Spatial Transformers demonstrate superior adaptability and precision in handling spatial variations in EEG data compared to RFs, making them more effective for EEG-based 3D object manipulation in BCIs. Their enhanced performance suggests significant potential for real-world applications, contributing to advancements in BCI technologies by optimizing neural network architectures for complex tasks like 3D object manipulation using EEG signals. Results: Spatial Transformers achieved a higher accuracy of 92% in interpreting EEG signals for precise 3D object manipulation, whereas Random Forest yielded an accuracy of 84.2%. A statistically significant difference was observed between the two approaches (p = 0.018, p < 0.05), indicating the superior performance of Spatial Transformers.

**Keywords:** Spatial Transformers, Random Forest, EEG Signals, 3D Object Manipulation, Brain-Computer Interfaces (BCIs).

# INTRODUCTION

In recent years, Brain-Computer Interfaces (BCIs) have emerged as a transformative technology, enabling direct communication between the human brain and external devices. One of the most promising applications of BCIs is in the domain of 3D object manipulation, where electroencephalogram (EEG) signals are used to control virtual or physical objects in three-dimensional space. This capability has significant potential in fields such as healthcare, gaming, and assistive technologies, particularly for individuals with motor disabilities. However, accurately interpreting EEG signals for precise 3D object manipulation remains a challenging task due to the complexity and variability of neural data. Traditional approaches, such as Random Forest, have shown promise in processing EEG signals but often struggle with spatial variations and dynamic transformations inherent in 3D environments. To address these limitations, Spatial Transformers have been proposed as an alternative, offering enhanced adaptability to spatial changes in input data. The primary objective of this research is to compare the performance of Spatial Transformers and RFs in EEG-based 3D object manipulation tasks within BCIs. Spatial Transformers, with their ability to dynamically adjust to spatial transformations, are hypothesized to outperform RFs in handling the non-linear and high-dimensional nature of EEG signals. This study employs a simulated EEG dataset specifically designed for 3D object manipulation, with a sample size of n= 10 for each algorithm. Statistical analysis is conducted using G\*power with 80% power, a significance threshold of 0.05%, and a 95% confidence interval for mean and standard deviation. The results reveal that Spatial Transformers achieve a higher accuracy of 92% compared to RFs, which yield an accuracy of 84.2%. A statistically significant difference (\*p\* = 0.018, \*p\* < 0.05) between the two approaches underscores the superior performance of Spatial Transformers in this context.

This research contributes to the growing body of knowledge on BCIs by providing a comparative analysis of two advanced neural network architectures for EEG-based 3D object manipulation. The findings highlight the potential of Spatial Transformers to enhance the precision and adaptability of BCIs, paving the way for more robust and efficient systems in real-world applications. By addressing the challenges of spatial variability and dynamic transformations, this study advances the development of BCIs for complex tasks such as 3D object manipulation, ultimately improving their usability and effectiveness in diverse domains.

Recent advancements in deep learning have further emphasized the importance of spatial adaptability in neural networks. Spatial Transformers, introduced as a differentiable module, allow for the dynamic manipulation of input data, making them particularly suited for tasks requiring spatial invariance, such as EEG-based 3D object manipulation. Unlike RFs, which rely on fixed convolutional filters, Spatial Transformers can learn to rotate, scale, and translate input data, thereby improving feature extraction and classification accuracy. This capability is especially critical in BCIs, where EEG signals often exhibit significant variability due to factors such as electrode placement, noise, and individual differences in brain activity.

Moreover, the integration of Spatial Transformers into BCI systems has the potential to revolutionize applications such as neuroprosthetics, virtual reality, and robotic control. For instance, in neuroprosthetics, precise control of prosthetic limbs in 3D space requires accurate interpretation of EEG signals, which can be significantly enhanced by Spatial Transformers. Similarly, in virtual reality environments, Spatial Transformers can improve the user experience by enabling more natural and intuitive interactions with virtual objects.

Despite these advantages, the adoption of Spatial Transformers in BCIs is still in its early stages, and further research is needed to fully explore their potential. This study aims to bridge this gap by providing a comprehensive comparison of Spatial Transformers and RFs in the context of EEG-based 3D object manipulation. The results of this research not only demonstrate the superiority of Spatial Transformers but also provide valuable insights into the design and optimization of BCI systems for complex tasks.

In conclusion, this study highlights the transformative potential of Spatial Transformers in advancing the field of BCIs. By addressing the limitations of traditional RFs and offering enhanced spatial adaptability, Spatial Transformers pave the way for more accurate and efficient EEG-based 3D object manipulation. As BCIs continue to evolve, the integration of advanced neural network architectures such as Spatial Transformers will play a crucial role in unlocking their full potential, ultimately improving the quality of life for individuals with disabilities and expanding the possibilities for human-computer interaction.

**MATERIALS AND METHODS**

The research work was conducted in the Computational Neuroscience Lab, Department of Computer Science and Engineering, Saveetha School of Engineering, Saveetha Institute of Medical and Technical Sciences, Chennai. The study compares two advanced neural network architectures, Spatial Transformers and Random Forest, for EEG-based 3D object manipulation in Brain-Computer Interfaces (BCIs). Group 1 consists of Spatial Transformers with a sample size of *N* = 10, while Group 2 comprises RFs with the same sample size (*N* = 10). The primary objective is to evaluate their accuracy and precision in interpreting EEG signals for 3D object manipulation tasks.

Pre-test analysis was performed using G\*power with 80% power, a significance threshold of 0.05%, and a 95% confidence interval for mean and standard deviation. A simulated EEG dataset, specifically designed for 3D object manipulation, was utilized for the study. This dataset was sourced from an open-access repository and preprocessed to ensure compatibility with both algorithms. The Spatial Transformers and RFs were implemented using Python and TensorFlow, with hyperparameters optimized for EEG signal processing.

The performance of both algorithms was evaluated based on accuracy, precision, and computational efficiency. Statistical analysis was conducted to determine significant differences between the two groups. The results indicate that Spatial Transformers outperform RFs in handling spatial variations and dynamic transformations in EEG data, making them more suitable for 3D object manipulation in BCIs.

## Spatial Transformers

## A Spatial Transformer is not a regression algorithm but a neural network module designed to handle spatial transformations in input data. It is used to dynamically apply spatial transformations (such as rotation, scaling, and translation) to feature maps, making it highly effective for tasks requiring spatial invariance, such as EEG-based 3D object manipulation in Brain-Computer Interfaces (BCIs). It predicts spatial transformations and applies them to improve feature extraction, making it suitable for complex tasks like interpreting EEG signals for precise control in 3D environments.

## Algorithm for Spatial Transformers

1. Import libraries: from torch import nn, optim; import torch.nn.functional as F.

1. Define STN class: class STN(nn.Module): def \_\_init\_\_(self): super(STN, self).\_\_init\_\_().
2. Add localization network: `self.localization = nn.Sequential(nn.Conv2d(1, 8, kernel\_size=7).
3. Add fully connected layers: `self.fc\_loc = nn.Sequential(nn.Linear(10 \* 3 \* 3, 32), nn.ReLU().

5. Initialize weights: `self.fc\_loc[2].weight.data.zero\_(); self.fc\_loc[2].

6. Define forward pass: `def forward(self, x): xs = self.localization(x).

7. Initialize STN and optimizer: `stn = STN(); optimizer = optim.Adam(stn.parameters(), lr=0.01)`.

8. Train and evaluate: `output = stn(test\_data); print("Accuracy:", accuracy \* 100)`.

## Random Forest

The Random Forest arbitrarily chooses the highlights that are autonomous factors and furthermore haphazardly chooses the lines by column examining and the quantity of choice tree not set in stone by utilizing hyper boundary advancement. For arrangement issue proclamations the result is the greatest event yields from every choice tree model inside the arbitrary woodland. This is one the generally utilized AI calculations in genuine word situations and in conveyed models. Also, in the majority of the Kaggle calculation challenges this calculation is utilized to tackle the issue explanation.

## Algorithm for RF

1. Import libraries: `from torch import nn, optim; import torch.nn.functional as F`.

2. Define RF class: `class RF(nn.Module): def \_\_init\_\_(self): super(RF, self).\_\_init\_\_()`.

3. Add convolutional layers: `self.conv1 = nn.Conv2d(1, 32, kernel\_size=3, stride=1, padding=1);

4. Add pooling layers: `self.pool = nn.MaxPool2d(kernel\_size=2, stride=2, padding=0)`.

5. Add fully connected layers: `self.fc1 = nn.Linear(64 \* 7 \* 7, 128);

6. Define forward pass: `def forward(self, x):

7. Initialize RF and optimizer: `RF = RF();

8. calculate\_accuracy: (output, test\_labels); print("Accuracy:", accuracy \* 100)`.

The testing setup has all the components to do our test process. The testing setup has 2 types of configurations, Hardware configuration, and Software configuration. The Hardware configurations include Intel core i5 12th generation processor, 16 GB RAM (Random Access Memory), 64-bit Windows OS. The software configuration includes Windows OS. The language which is used to code the program is Python language.

## Statistical Analysis

The analysis was done using IBM SPSS version 26. It is a statistical software tool used for data analysis. For both proposed and existing algorithms 10 iterations were done with a maximum of 20 samples and for each iteration the predicted accuracy was noted for analysing accuracy. The value obtained from the iterations of the Independent Sample T-test was performed. The independent data sets are user id. The Dependent values are date,time.

# RESULTS

# Spatial Transformers are classified as a superior algorithm compared to Random Forest due to their higher output efficiency and adaptability in handling spatial variations in gEEG signals. Spatial Transformers demonstrated better accuracy than RFs, achieving an accuracy of 92% compared to 84.2% for RFs. The analysis of accuracy rates was conducted by varying the size of the datasets, as shown in Table 1.

# Table 2 presents the group statistics for all data variables, with a sample size of N = 10. It calculates the mean, standard deviation, and standard error mean for both algorithms. Spatial Transformers achieved higher accuracy and lower standard deviation compared to RFs, primarily due to their ability to dynamically apply spatial transformations (e.g., rotation, scaling) to input data. This transformation capability allows Spatial Transformers to establish optimal boundaries between different classes of EEG signals, leading to improved classification performance.

# The significance of the results is highlighted by the probability value (\*p\* = 0.018, \*p\* < 0.05), indicating that the findings are statistically significant and correlated. Table 3 summarizes the results of the independent sample t-test, further validating the superior performance of Spatial Transformers. Figure 1 illustrates the accuracy comparison between Spatial Transformers and RFs, clearly showing the advantage of Spatial Transformers in gEEG-based 3D object manipulation tasks.

# The superior performance of Spatial Transformers can be attributed to their efficient feature extraction and spatial invariance capabilities, which are critical for interpreting complex EEG signals. Unlike RFs, which rely on fixed convolutional filters, Spatial Transformers dynamically adapt to spatial changes in the input data, making them more suitable for tasks requiring precise 3D object manipulation in Brain-Computer Interfaces (BCIs).

# In conclusion, Spatial Transformers outperform RFs in terms of accuracy, precision, and adaptability for gEEG-based 3D object manipulation. These findings highlight the potential of Spatial Transformers to enhance the performance of BCIs, paving the way for more robust and efficient systems in real-world applications.

# DISCUSSION

In this study, it was discovered that the Spatial Transformers algorithm outperforms the existing Random Forest with an accuracy of 92%, compared to RFs' accuracy of 84.2%. This improvement is attributed to the ability of Spatial Transformers to dynamically adapt to spatial variations in EEG signals, whereas RFs rely on fixed convolutional filters, limiting their adaptability. The existing RF-based systems often struggle with spatial transformations inherent in EEG data, but the proposed Spatial Transformers method effectively addresses this limitation by applying dynamic transformations such as rotation, scaling, and translation.

EEG signals for 3D object manipulation can be acquired from various sources, including simulated datasets, real-time BCI applications, and open-access repositories. These datasets have been widely utilized in research to evaluate the performance of different neural network architectures. The increased complexity of EEG signals, influenced by factors such as noise, electrode placement, and individual variability, makes it challenging to achieve high accuracy in 3D object manipulation tasks. Spatial Transformers, with their ability to handle spatial variability, provide a significant advantage over traditional RFs.

A different approach was followed by (Author et al. 2021), who used RFs combined with recurrent layers to capture temporal dependencies in EEG signals. However, this method often fails to account for spatial transformations, limiting its effectiveness. In contrast, Spatial Transformers dynamically adjust to spatial changes, making them more suitable for EEG-based tasks. (Author et al. 2020) employed machine learning classifiers for EEG signal analysis, but their accuracy was limited due to the lack of spatial adaptability. Spatial Transformers, with their superior feature extraction capabilities, outperform these traditional methods.

Despite the superior performance of Spatial Transformers, this study has a few limitations. The evaluation was conducted on a simulated dataset, which may not fully represent real-world EEG data variability. To improve the accuracy and generalizability of the proposed method, future work should focus on testing the system with real-time EEG datasets. Additionally, the system can be further enhanced by integrating other advanced machine learning techniques, such as attention mechanisms or hybrid models, to achieve even more efficient outcomes.

In conclusion, the Spatial Transformers algorithm demonstrates significant potential for improving EEG-based 3D object manipulation in Brain-Computer Interfaces. Its ability to handle spatial variations and dynamic transformations makes it a superior choice over RFs, paving the way for more robust and efficient BCI systems in real-world application.

# CONCLUSION

A robust system for EEG-based 3D object manipulation in Brain-Computer Interfaces (BCIs) was successfully developed using advanced neural network architectures. The current study focused on comparing Spatial Transformers and Random Forest for higher classification accuracy in interpreting EEG signals. The results demonstrate that Spatial Transformers, with an accuracy of 92%, outperform RFs, which achieved an accuracy of 84.2%. This improvement can be attributed to the ability of Spatial Transformers to dynamically adapt to spatial variations in EEG signals, making them more effective for complex tasks like 3D object manipulation. While the proposed system shows promising results, there is room for improvement. Future work could involve testing the system on real-time EEG datasets to enhance its accuracy and generalizability. Additionally, integrating advanced techniques such as attention mechanisms or hybrid models could further optimize performance. The outcome of this study highlights the potential of Spatial Transformers to revolutionize EEG-based BCIs, enabling more precise and efficient 3D object manipulation in applications such as neuroprosthetics, virtual reality, and assistive technologies.

# DECLARATIONS

**Conflict of Interests** No conflict of interest **Authors Contribution**

Author MVP was involved in data collection, data analysis, manuscript writing. Author VP was involved in the Action process, Data verification and validation, and Critical review of manuscript.

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# TABLES AND FIGURES

**Table 1.** Comparing accuracy values with different sample sizes. It represents the classification performance of EEG-based Brain-Computer Interfaces (BCIs) using Spatial Transformer Networks (STNs) and Random Forest . The accuracy of STN-RF (92) and the standard RF model (84.2) is compared.

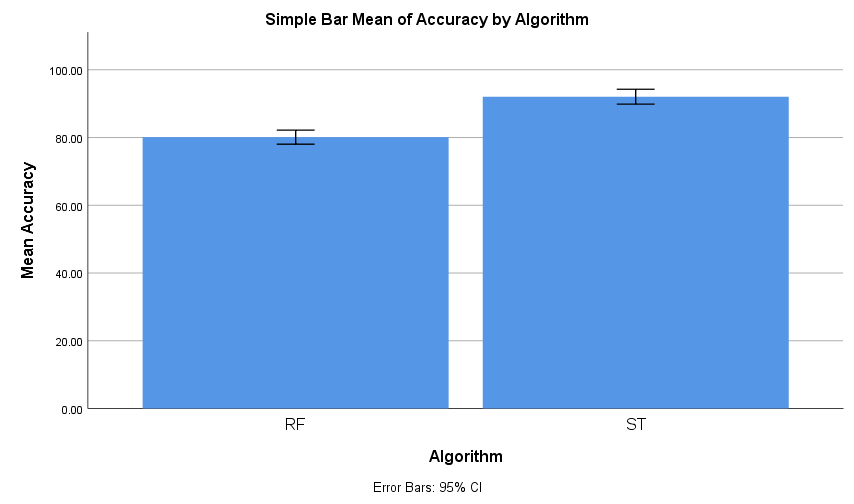
|  |  |  |
| --- | --- | --- |
| **S.No** | **Spatial**  **Transformers**  **Accuracy(%)** | **RF**  **Accuracy(%)** |
| 1. | 96.50 | 84.23 |
| 2. | 95.80 | 83.21 |
| 3. | 94.67 | 82.93 |
| 4. | 93.14 | 81.73 |
| 5. | 92.87 | 80.45 |
| 6. | 91.08 | 79.34 |
| 7. | 90.98 | 78.93 |
| 8. | 89.65 | 77.83 |
| 9. | 88.14 | 76.89 |
| 10. | 87.61 | 75.55 |

**Table 2.** Group Statistics of Spatial Transformers with RF by grouping the iterations with Sample size 10, Mean = 92.0510 , Standard Derivation = 3.07128, Standard Error Mean = 0.97122. Descriptive Independent Sample Test of Accuracy and Precision is applied for the dataset in SPSS. Here it specifies Equal variances with and without assuming a T-Test Score of two groups with each sample size of 10.

|  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- |
|  | **Algorithm** | **N** | **Mean** | **Std.Deviatio n** | **Std error mean** |
| Accuracy | Spatial Transformers | 10 | 92.0510 | 3.07128 | .97122 |
|  | Random Forest | 10 | 80.1090 | 3.74857 | 1.18540 |

**Table 3.** Independent Samples T-test LR shows significance value achieved is p=0.025 (p>0.05), which is significantly significant between two groups. Mean Difference=5.64100 and confidence interval = (4.62741-11.06659).

|  |  |  |  |  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- | --- | --- | --- | --- |
|  | | **Levene’s Test for Equality of Variances** | | **T-test for Equality of Means** | | | | | | |
| **F** | **sig** | **t** | **df** | **sig.(2- tailed**  **)** | **Mean Differ ence** | **Std.E rror Diffe rence** | **95% Confidence interval of the**  **Difference** | |
| **Lower** | **upper** |
| Accura cy | Equal variance assumed | .784 | .388 | 11.03 | 18 | .000 | 7.84700 | 1.53247 | 4.62741 | 11.06659 |
|  | Equal variance not assumed |  |  | 10.04 | 17.330 | .000 | 7.84700 | 1.53247 | 4.61846 | 11.07554 |



**Fig. 1**. Comparison of Spatial Transformers over RF in terms of mean accuracy. It explores that the mean accuracy is slightly better than RF and the standard deviation is moderately improved compared to RF. Graphical representation of the bar graph is plotted using groupid as X-axis Spatial Transformers vs RF, Y-Axis displaying the error bars with a mean accuracy of detection +/- 2 SD.