

Mathematical introduction to Compressed Sensing

Lesson 1 : measurements and sparsity

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Aim of the course: analyze high-dimensional data

- ① Understand **low-dimensional structures** in high-dimensional spaces
- ② reveal this structure via appropriate **measurements**
- ③ construct **efficient algorithms** to learn this structure

Tools:

- ① approximation theory
- ② probability theory
- ③ convex optimization algorithms

Rem.: Register at

<http://datascience-x-master-paris-saclay.fr>

First lesson is about:

Two central ideas:

- ① Sparsity
- ② measurements

through three examples:

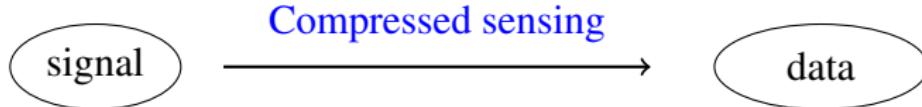
- ① Single pixel camera
- ② face recognition
- ③ Financial data

What is Compressed Sensing?

Classical data acquisition system in **two steps**:



Compressed sensing makes it in **one step**:



In french: Compressed Sensing = "acquisition comprimée"

Q: How is it possible? A: Construct clever measurements!

x : a signal (finite dimensional vector, say $x \in \mathbb{R}^N$)

Take m linear measurements of signal x :

$$y_i = \langle x, \textcolor{red}{X}_i \rangle, \quad i = 1, \dots, m$$

where:

- ① X_i : i-th measurement vector (in \mathbb{R}^N),
- ② y_i : i-th measurement (= data = observation).

Problem: reconstruct x from the measurements $(y_i)_{i=1}^m$ and the measurement vectors $(X_i)_{i=1}^m$ with m as small as possible.

Matrix version of Compressed Sensing

We denote

$$y = \begin{pmatrix} y_1 \\ \vdots \\ y_m \end{pmatrix} \in \mathbb{R}^m \quad \text{and} \quad A = \begin{pmatrix} X_1^\top \\ \vdots \\ X_m^\top \end{pmatrix} \in \mathbb{R}^{m \times N}$$

y : measurements vector and A : measurements matrix

Problem: find x such that $y = Ax$ when $m \ll N$

$$\boxed{A} = \boxed{x} \quad \boxed{y}$$

CS = solve a highly undetermined linear system

Sparsity = low-dimensional structure

Since $m < N$ there is **no unique solution** to the problem $y = Ax \Rightarrow$ no hope to reconstruct x from the m measurements $y_i = \langle x, X_i \rangle$.

Idea: Signals to recover have some low-dimensional structure. We assume that x is **sparse**.

Definition

Support of $x = (x_1, \dots, x_N)^\top$:

$$\text{supp}(x) = \{j \in \{1, \dots, N\} : x_j \neq 0\}$$

Size of the support of x :

$$\|x\|_0 = |\text{supp}(x)|$$

x is **s -sparse** when $\|x\|_0 \leq s$.

Sparsity and the undetermined system $y = Ax$

Idea: Maybe the kernel of A is in such a position that the sparsest solution to $y = Ax$ is x itself?

Procedure: Look for the sparsest solution of the system $y = Ax$:

$$\hat{x}_0 \in \underset{At=y}{\operatorname{argmin}} \|t\|_0 \quad (1)$$

which looks for vector t with the shortest support in the affine set

$$\{t \in \mathbb{R}^N : At = y\} = x + \ker(A).$$

Idea: Denote $\Sigma_s = \{t \in \mathbb{R}^N : \|t\|_0 \leq s\}$. If $\Sigma_s \cap (x + \ker(A)) = \{x\}$ then the sparsest element in $x + \ker(A)$ is x and so $\hat{x}_0 = x$

Definition

\hat{x}_0 is called the ℓ_0 -minimization procedure

(cf. Second lesson mardi 2 septembre)

Compressed sensing: problems statement

Problem 1: *Construct a minimal number of measurement vectors X_1, \dots, X_m such that one can reconstruct any s -sparse signal x from the m measurements $(\langle x, X_i \rangle)_{i=1}^m$.*

Problem 2: *Construct efficient algorithms that can reconstruct exactly any sparse signal x from the measurements $(\langle x, X_i \rangle)_{i=1}^m$.*

Is signal x really sparse?

Sparsity of signal x is the main assumption in Compressed Sensing (and more generally in high-dimensional statistics).

Q.: Is it true that "real signals" are sparse?

Three examples:

- ① images
- ② face recognition
- ③ financial data

Compressed Sensing in images

Sparse representation of images



An image is a:

- ➊ vector $f \in \mathbb{R}^{n \times n}$
- ➋ function $f : \{0, \dots, n - 1\}^2 \rightarrow \mathbb{R}$

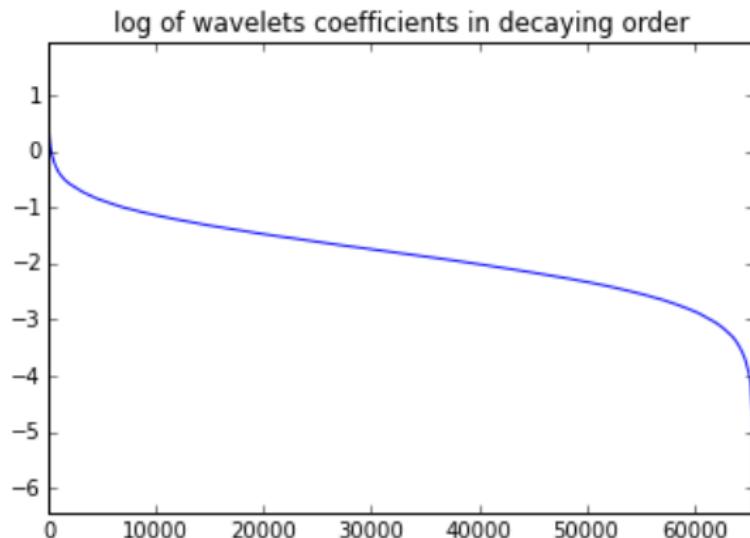
Images can be developed into basis: $f = \sum_{j=1}^{n^2} \langle f, \psi_j \rangle \psi_j$

Problem in approximation theory: Find basis (ψ_j) such that $(\langle f, \psi_j \rangle)_{j=1}^{n^2}$ is (approximatively) a sparse vector for real life images f .

Solution: Wavelets basis (cf. Gabriel Peyré course)

notebook: wavelet decomposition

Sparse representation of images



Graphics: Representation of $(\log |\langle f, \psi_j \rangle|)_{j=1}^{n^2}$ in a decaying order for $n = 256$ ($256^2 = 65.536$ coefficients).

Conclusion: When developed in an appropriate basis, images have an *almost* sparse representation.

Sparse representation of images



Idea: Compression of images by thresholding small wavelets coefficients (JPEG 2000).

Remark: these are the only three slides about approximation theory in this course!

Compressed sensing and images

Two differences with the CS framework introduced above:

- ① images are almost sparse
- ② images are (almost) sparse not in the canonical basis but in some other (wavelet) basis.

Two consequences:

- ① our procedures will be asked to "adapt" to this almost sparse situation:
stability property
- ② we need to introduce a **structured sparsity**: being sparse in some general basis.

Structured sparsity

Definition

Let $\mathcal{F} = \{f_1, \dots, f_p\}$ be a **dictionary** in \mathbb{R}^N . A vector $x \in \mathbb{R}^N$ is said **s -sparse in \mathcal{F}** when there exists $J \subset \{1, \dots, p\}$ such that

$$|J| \leq s \text{ and } x = \sum_{j \in J} \theta_j f_j.$$

In this case,

$$x = F\theta \text{ where } F = [f_1 | \dots | f_p] \in \mathbb{R}^{N \times p}$$

and $\theta \in \mathbb{R}^p$ is a s -sparse in the canonical basis.

For CS measurements, one has:

$$y = Ax = AF\theta$$

where $\theta \in \Sigma_s$ and so one just has to replace the measurement matrix A by AF .

Conclusion: All the course deals only with vectors that are sparse in the **canonical basis**.

What is a photos machine using CS?

It should take measurements like:



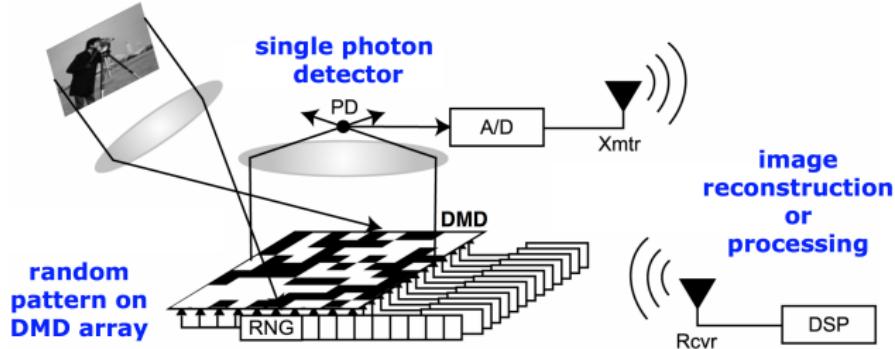
We take m measurements:

$$y_1 = \langle \text{Portrait}, \text{Noise} \rangle , \dots ,$$

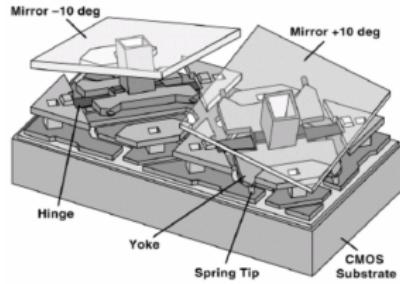
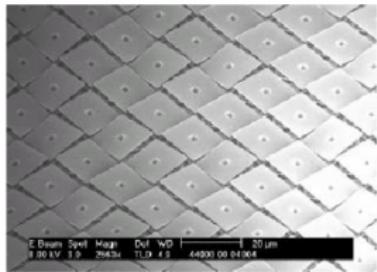
$$y_m = \langle \text{Portrait}, \text{Noise} \rangle$$

In particular, measurements y_1, \dots, y_m are real numbers that can be stored using only one pixel in the camera.

Single pixel camera from RICE University



DMD: digital micromirror device – **randomly** orientated



Single pixel camera from RICE University

target
65536 pixels



4096 measurements
(16%)



1300 measurements
(2%)



Example of reconstruction of an image using the single pixel camera.

Two problems:

- ① How do we choose the measurement vectors:  , … ,  ?
- ② Is there an efficient algorithm to reconstruct the signal from those few measurements?

CS in face Recognition

face recognition and Compressed Sensing

Database: $\mathcal{D} := \{(\phi_j, \ell_j) : 1 \leq j \leq N\}$ where :

- ① $\phi_j \in \mathbb{R}^m$ is a vector representation of the j -th image, (for instance, concatenation of the images pixels value)
- ② $\ell_j \in \{1, \dots, C\}$ is a label referring to a person

A same person may be represented in \mathcal{D} several times from various angles, luminosity, etc..

Problem: Given a new image $y \in \mathbb{R}^m$, we want to label it with an element from the set $\{\ell_j, j = 1, \dots, C\}$

"Classical" solution: use multi-class classification algorithm.

Here: Face recognition as a CS problem.

The sparsity assumption in face recognition

Empirical observation: If for all of the C individuals one has:

- ① a large enough number of images,
- ② enough diversity in terms of angles and brightness

then for any new image $y \in \mathbb{R}^m$ of individual number $i \in \{1, \dots, C\}$, one expect that

$$y \approx \sum_{j: \ell_j = i} \phi_j \mathbf{x}_j.$$

Consequence: We assume that a new image $y \in \mathbb{R}^m$ can be written as

$$y = \Phi \mathbf{x} + \zeta$$

where:

- ① $\Phi = [\Phi_1 | \Phi_2 | \dots | \Phi_C]$ and $\Phi_i = [\phi_j : \ell_j = i]$ for any $i \in \{1, \dots, C\}$,
- ② $\mathbf{x} = [\mathbf{0}^\top | \mathbf{0}^\top | \dots | \mathbf{x}_i^\top | \mathbf{0}^\top | \dots | \mathbf{0}^\top]^\top$ where \mathbf{x}_i is the restriction of \mathbf{x} to the columns of Φ_i in Φ
- ③ $\zeta \in \mathbb{R}^m$ error due to linear approximation of y by columns in Φ .

Face recognition as a noisy CS problem

Compare with the benchmark CS setup, one has three difference:

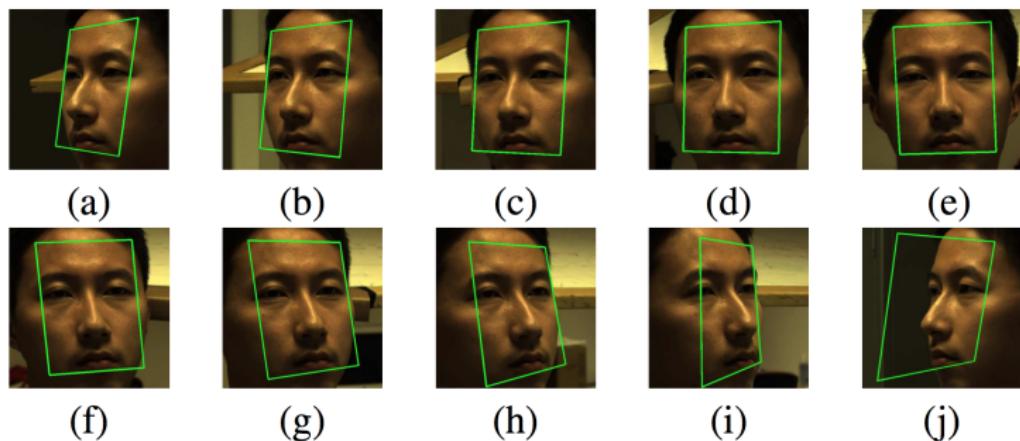
- ① there is an additional noise term ζ
- ② the sparsity assumption on x is stronger here: x is block-sparse
- ③ depending on the control one has on the database, we may or may not have the ability to choose (in a restricted way) the measurement matrix.

Three consequences:

- ① our procedures will be asked to deal with noisy data: **robustness property**
- ② we will design procedures taking advantages of more "advanced" sparsity like the block-sparsity one
- ③ when one is in a situation where there is no control on the choice of measurement vectors then one can try several procedures and see how they behave.

Construction of a measurement matrix in face recognition

Various angles:



Various brightness:



CS in Finance

Finance and CS

Problem: We observe the performances of a portfolio every minute:
 y_1, \dots, y_m . We would like to know how it is structured (shares and quantity).
Data: In addition to y_1, \dots, y_m , we know the values of all shares at any time:

95 Save Defaults		96 News		97 Feedback		Global Commodity Prices			
Movers	Units	Chg	NY 14:30	Cal	Spreads	Avg	Performance	%YTD	USD
1) Energy	Units	2Day	Price	Net Chg	%Chg	Time			
10) NYMEX WTI Crude	d \$/bbl		88.70	-0.58	-0.65%	9:03	-10.25%	-10.25%	
11) ICE Brent Crude	d \$/bbl		111.19	-0.51	-0.46%	9:03	+3.55%	+3.55%	
12) NYMEX Gasoline	d USD/gal		273.43	-2.02	-0.73%	9:03	+1.79%	+1.79%	
13) NYMEX Heat Oil	d USD/gal		306.70	-0.81	-0.26%	9:03	+4.50%	+4.50%	
14) ICE Gasoil	d \$/mt		952.50	-1.00	-0.10%	9:03	+2.90%	+2.90%	
15) NYMEX Nat Gas	d \$/MMBtu		3.756	+0.037	+0.99%	9:03	+25.66%	+25.66%	
2) Metals									
20) Spot Gold	\$/t oz		1732.10	+0.38	+0.02%	9:13	+10.68%	+10.68%	
21) Spot Silver	\$/t oz		33.12	+0.00	+0.00%	9:13	+18.97%	+18.97%	
22) Spot Platinum	\$/t oz		1575.63	-2.33	-0.15%	9:13	+13.00%	+13.00%	
23) Spot Palladium	\$/t oz		642.60	+0.90	+0.14%	9:10	-1.61%	-1.61%	
24) LME 3mth Aluminium	d \$/mt		1977.00	y +26.00	+1.33%	11/19	-2.13%	-2.13%	
25) LME 3mth Copper	d \$/mt		7804.00	y +199.00	+2.62%	11/19	+2.68%	+2.68%	
3) Agriculture									
30) CBOT Corn	d USD/bsh		742.00	-0.50	-0.07%	9:03	+14.23%	+14.23%	
31) CBOT Wheat	d USD/bsh		855.00	-2.75	-0.32%	9:02	+28.61%	+28.61%	
32) CBOT Soybeans	d USD/bsh		1391.25	-3.50	-0.25%	9:03	+16.08%	+16.08%	
33) ICE Coffee	d USD/lb		156.45	-0.95	-0.60%	9:03	-33.72%	-33.72%	
34) ICE Sugar	d USD/lb		19.81	-0.13	-0.65%	9:03	-14.98%	-14.98%	
35) ICE Cotton	d USD/lb		72.00	-0.06	-0.08%	9:02	-21.63%	-21.63%	

Finance and CS

$x_{i,j}$: value of share j at time i . We have the following data:

$t = 1 : y_1 : \text{portfolio value} \quad (x_{1,j})_{j=1}^N : \text{shares values}$

$t = 2 : y_2 : \text{portfolio value} \quad (x_{2,j})_{j=1}^N : \text{shares values}$

.....

$t = m : y_m : \text{portfolio value} \quad (x_{m,j})_{j=1}^N : \text{shares values}$

Sparsity assumption: The portfolio contains only a limited number of shares and its structure did not change during the observation time.

Problem formulation: find $x \in \mathbb{R}^N$ such that $y = Ax$ where

$$y = (y_i)_{i=1}^m \text{ and } A = (x_{i,j} : 1 \leq i \leq m, 1 \leq j \leq N)$$

and x is supposed to be sparse.

Noisy data – robust procedures

In the case of noisy data,

$$y = Ax + \zeta$$

we want procedures that are robust to this noise perturbation.

Definition (Robustness)

We say that a procedure $\Delta : \mathbb{R}^m \rightarrow \mathbb{R}^N$ is **robust of order s** when for any s -sparse vector $x \in \mathbb{R}^N$ and any noise $\zeta \in \mathbb{R}^m$, one has

$$\|x - \Delta(Ax + \zeta)\|_2 \leq c_0 \|\zeta\|_2$$

where c_0 is some absolute constant.

Approximatively sparse signal – stable procedures

In cases where signal x is only "approximatively sparse" that is

$$\min_{z \in \Sigma_s} \|x - z\|_1$$

is not exactly equal to zero but "small", we want procedures to perform still well.

Definition (Stability)

We say that a procedure $\Delta : \mathbb{R}^m \rightarrow \mathbb{R}^N$ is **stable of order s** when for any vector $x \in \mathbb{R}^N$ one has

$$\|x - \Delta(Ax)\|_2 \leq c_0 \frac{\min_{z \in \Sigma_s} \|x - z\|_1}{\sqrt{s}}$$

where c_0 is some absolute constant.

Stable and robust procedures

Definition (Stability and robustness)

We say that a procedure $\Delta : \mathbb{R}^m \rightarrow \mathbb{R}^N$ is **robust and stable of order s** when for any $x \in \mathbb{R}^N$ and $\zeta \in \mathbb{R}^m$, one has

$$\|x - \Delta(Ax + \zeta)\|_2 \leq c_0 \frac{\min_{z \in \Sigma_s} \|x - z\|_1}{\sqrt{s}} + c_0 \|\zeta\|_2$$

where c_0 is some absolute constant.

CS and high-dimensional statistics

Definition

We say that a statistical problem is a **high-dimensional statistical problem** when one has to estimate a N -dimensional parameter using m observations and $m < N$.

- ① CS is therefore a high-dimensional statistical problem.
- ② Noisy CS is exactly the linear regression statistical model when the noise is assumed to be random.