Practical Machine Learning FInal

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Installing packages, loading libraries, and setting the seed for reproduceability

```
library(caret)

## Loading required package: lattice

## Loading required package: ggplot2

library(lattice)
library(ggplot2)
library(randomForest)

## randomForest 4.6-12

## Type rfNews() to see new features/changes/bug fixes.

##
## Attaching package: 'randomForest'

## The following object is masked from 'package:ggplot2':
##
##     margin
```

randomForest 4.6-10

Type rfNews() to see new features/changes/bug fixes.

```
library(rpart)
library(rpart.plot)

# setting the overall seed for reproduceability
set.seed(1234)
```

Loading data sets and preliminary cleaning

First we want to load the data sets into R and make sure that missing values are coded correctly.

Irrelevant variables will be deleted.

Results will be hidden from the report for clarity and space considerations.

```
# After saving both data sets into my working directory
# Some missing values are coded as string "#DIV/0!" or "" or "NA" - these
will be changed to NA.
# We notice that both data sets contain columns with all missing values -
these will be deleted.

# Loading the training data set into my R session replacing all missing with
"NA"
trainingset <- read.csv("C:/pml-training.csv", na.strings=c("NA","#DIV/0!",
""))

# Loading the testing data set
testingset <- read.csv('C:/pml-testing.csv', na.strings=c("NA","#DIV/0!",
""))

# Check dimensions for number of variables and number of observations
dim(trainingset)

## [1] 19622   160

dim(testingset)

## [1]  20 160

# Delete columns with all missing values
trainingset<-trainingset[,colSums(is.na(trainingset)) == 0]
testingset <-testingset[,colSums(is.na(testingset)) == 0]

# Some variables are irrelevant to our current project: user_name,
raw_timestamp_part_1, raw_timestamp_part_,2 cvtd_timestamp, new_window, and
num_window (columns 1 to 7). We can delete these variables.
trainingset   <-trainingset[,-c(1:7)]
testingset <-testingset[,-c(1:7)]

# and have a look at our new datasets:
dim(trainingset)

## [1] 19622    53
```

```r
dim(testingset)
```

```
## [1] 20 53
```

```r
head(trainingset)
```

```
##   roll_belt pitch_belt yaw_belt total_accel_belt gyros_belt_x gyros_belt_y
## 1      1.41       8.07    -94.4                3         0.00         0.00
## 2      1.41       8.07    -94.4                3         0.02         0.00
## 3      1.42       8.07    -94.4                3         0.00         0.00
## 4      1.48       8.05    -94.4                3         0.02         0.00
## 5      1.48       8.07    -94.4                3         0.02         0.02
## 6      1.45       8.06    -94.4                3         0.02         0.00
##   gyros_belt_z accel_belt_x accel_belt_y accel_belt_z magnet_belt_x
## 1        -0.02          -21            4           22            -3
## 2        -0.02          -22            4           22            -7
## 3        -0.02          -20            5           23            -2
## 4        -0.03          -22            3           21            -6
## 5        -0.02          -21            2           24            -6
## 6        -0.02          -21            4           21             0
##   magnet_belt_y magnet_belt_z roll_arm pitch_arm yaw_arm total_accel_arm
## 1           599          -313     -128      22.5    -161              34
## 2           608          -311     -128      22.5    -161              34
## 3           600          -305     -128      22.5    -161              34
## 4           604          -310     -128      22.1    -161              34
## 5           600          -302     -128      22.1    -161              34
## 6           603          -312     -128      22.0    -161              34
##   gyros_arm_x gyros_arm_y gyros_arm_z accel_arm_x accel_arm_y accel_arm_z
## 1        0.00        0.00       -0.02        -288         109        -123
## 2        0.02       -0.02       -0.02        -290         110        -125
## 3        0.02       -0.02       -0.02        -289         110        -126
## 4        0.02       -0.03        0.02        -289         111        -123
## 5        0.00       -0.03        0.00        -289         111        -123
## 6        0.02       -0.03        0.00        -289         111        -122
##   magnet_arm_x magnet_arm_y magnet_arm_z roll_dumbbell pitch_dumbbell
## 1         -368          337          516      13.05217      -70.49400
## 2         -369          337          513      13.13074      -70.63751
## 3         -368          344          513      12.85075      -70.27812
## 4         -372          344          512      13.43120      -70.39379
## 5         -374          337          506      13.37872      -70.42856
## 6         -369          342          513      13.38246      -70.81759
##   yaw_dumbbell total_accel_dumbbell gyros_dumbbell_x gyros_dumbbell_y
## 1    -84.87394                   37                0            -0.02
## 2    -84.71065                   37                0            -0.02
## 3    -85.14078                   37                0            -0.02
## 4    -84.87363                   37                0            -0.02
## 5    -84.85306                   37                0            -0.02
## 6    -84.46500                   37                0            -0.02
##   gyros_dumbbell_z accel_dumbbell_x accel_dumbbell_y accel_dumbbell_z
## 1             0.00             -234               47             -271
```

```
## 2            0.00             -233              47              -269
## 3            0.00             -232              46              -270
## 4           -0.02             -232              48              -269
## 5            0.00             -233              48              -270
## 6            0.00             -234              48              -269
##   magnet_dumbbell_x magnet_dumbbell_y magnet_dumbbell_z roll_forearm
## 1              -559               293               -65         28.4
## 2              -555               296               -64         28.3
## 3              -561               298               -63         28.3
## 4              -552               303               -60         28.1
## 5              -554               292               -68         28.0
## 6              -558               294               -66         27.9
##   pitch_forearm yaw_forearm total_accel_forearm gyros_forearm_x
## 1         -63.9        -153                  36            0.03
## 2         -63.9        -153                  36            0.02
## 3         -63.9        -152                  36            0.03
## 4         -63.9        -152                  36            0.02
## 5         -63.9        -152                  36            0.02
## 6         -63.9        -152                  36            0.02
##   gyros_forearm_y gyros_forearm_z accel_forearm_x accel_forearm_y
## 1            0.00           -0.02             192             203
## 2            0.00           -0.02             192             203
## 3           -0.02            0.00             196             204
## 4           -0.02            0.00             189             206
## 5            0.00           -0.02             189             206
## 6           -0.02           -0.03             193             203
##   accel_forearm_z magnet_forearm_x magnet_forearm_y magnet_forearm_z
## 1            -215              -17              654              476
## 2            -216              -18              661              473
## 3            -213              -18              658              469
## 4            -214              -16              658              469
## 5            -214              -17              655              473
## 6            -215               -9              660              478
##   classe
## 1      A
## 2      A
## 3      A
## 4      A
## 5      A
## 6      A
```

```r
head(testingset)
```

```
##   roll_belt pitch_belt yaw_belt total_accel_belt gyros_belt_x gyros_belt_y
## 1    123.00      27.00    -4.75               20        -0.50        -0.02
## 2      1.02       4.87   -88.90                4        -0.06        -0.02
## 3      0.87       1.82   -88.50                5         0.05         0.02
## 4    125.00     -41.60   162.00               17         0.11         0.11
## 5      1.35       3.33   -88.60                3         0.03         0.02
## 6     -5.92       1.59   -87.70                4         0.10         0.05
```

```
##   gyros_belt_z accel_belt_x accel_belt_y accel_belt_z magnet_belt_x
## 1        -0.46          -38           69         -179           -13
## 2        -0.07          -13           11           39            43
## 3         0.03            1           -1           49            29
## 4        -0.16           46           45         -156           169
## 5         0.00           -8            4           27            33
## 6        -0.13          -11          -16           38            31
##   magnet_belt_y magnet_belt_z roll_arm pitch_arm yaw_arm total_accel_arm
## 1           581          -382     40.7    -27.80     178              10
## 2           636          -309      0.0      0.00       0              38
## 3           631          -312      0.0      0.00       0              44
## 4           608          -304   -109.0     55.00    -142              25
## 5           566          -418     76.1      2.76     102              29
## 6           638          -291      0.0      0.00       0              14
##   gyros_arm_x gyros_arm_y gyros_arm_z accel_arm_x accel_arm_y accel_arm_z
## 1       -1.65        0.48       -0.18          16          38          93
## 2       -1.17        0.85       -0.43        -290         215         -90
## 3        2.10       -1.36        1.13        -341         245         -87
## 4        0.22       -0.51        0.92        -238         -57           6
## 5       -1.96        0.79       -0.54        -197         200         -30
## 6        0.02        0.05       -0.07         -26         130         -19
##   magnet_arm_x magnet_arm_y magnet_arm_z roll_dumbbell pitch_dumbbell
## 1         -326          385          481     -17.73748       24.96085
## 2         -325          447          434      54.47761      -53.69758
## 3         -264          474          413      57.07031      -51.37303
## 4         -173          257          633      43.10927      -30.04885
## 5         -170          275          617    -101.38396      -53.43952
## 6          396          176          516      62.18750      -50.55595
##   yaw_dumbbell total_accel_dumbbell gyros_dumbbell_x gyros_dumbbell_y
## 1    126.23596                    9             0.64             0.06
## 2    -75.51480                   31             0.34             0.05
## 3    -75.20287                   29             0.39             0.14
## 4   -103.32003                   18             0.10            -0.02
## 5    -14.19542                    4             0.29            -0.47
## 6    -71.12063                   29            -0.59             0.80
##   gyros_dumbbell_z accel_dumbbell_x accel_dumbbell_y accel_dumbbell_z
## 1            -0.61               21              -15               81
## 2            -0.71             -153              155             -205
## 3            -0.34             -141              155             -196
## 4             0.05              -51               72             -148
## 5            -0.46              -18              -30               -5
## 6             1.10             -138              166             -186
##   magnet_dumbbell_x magnet_dumbbell_y magnet_dumbbell_z roll_forearm
## 1               523              -528               -56          141
## 2              -502               388               -36          109
## 3              -506               349                41          131
## 4              -576               238                53            0
## 5              -424               252               312         -176
## 6              -543               262                96          150
##   pitch_forearm yaw_forearm total_accel_forearm gyros_forearm_x
```

```
## 1        49.30      156.0                  33           0.74
## 2       -17.60      106.0                  39           1.12
## 3       -32.60       93.0                  34           0.18
## 4         0.00        0.0                  43           1.38
## 5        -2.16      -47.9                  24          -0.75
## 6         1.46       89.7                  43          -0.88
##   gyros_forearm_y gyros_forearm_z accel_forearm_x accel_forearm_y
## 1           -3.34           -0.59            -110             267
## 2           -2.78           -0.18             212             297
## 3           -0.79            0.28             154             271
## 4            0.69            1.80             -92             406
## 5            3.10            0.80             131             -93
## 6            4.26            1.35             230             322
##   accel_forearm_z magnet_forearm_x magnet_forearm_y magnet_forearm_z
## 1            -149             -714              419              617
## 2            -118             -237              791              873
## 3            -129              -51              698              783
## 4             -39             -233              783              521
## 5             172              375             -787               91
## 6            -144             -300              800              884
##   problem_id
## 1          1
## 2          2
## 3          3
## 4          4
## 5          5
## 6          6
```

Partitioning the training data set to allow cross-validation

The training data set contains 53 variables and 19622 obs.

The testing data set contains 53 variables and 20 obs.

In order to perform cross-validation, the training data set is partionned into 2 sets: subTraining (75%) and subTest (25%).

This will be performed using random subsampling without replacement.

```
subsamples <- createDataPartition(y=trainingset$classe, p=0.75, list=FALSE)
subTraining <- trainingset[subsamples, ]
subTesting <- trainingset[-subsamples, ]
dim(subTraining)

## [1] 14718    53

dim(subTesting)
```

```
## [1] 4904   53
```

```r
head(subTraining)
```

```
##   roll_belt pitch_belt yaw_belt total_accel_belt gyros_belt_x gyros_belt_y
## 2      1.41       8.07    -94.4                3         0.02         0.00
## 3      1.42       8.07    -94.4                3         0.00         0.00
## 4      1.48       8.05    -94.4                3         0.02         0.00
## 5      1.48       8.07    -94.4                3         0.02         0.02
## 6      1.45       8.06    -94.4                3         0.02         0.00
## 7      1.42       8.09    -94.4                3         0.02         0.00
##   gyros_belt_z accel_belt_x accel_belt_y accel_belt_z magnet_belt_x
## 2        -0.02          -22            4           22            -7
## 3        -0.02          -20            5           23            -2
## 4        -0.03          -22            3           21            -6
## 5        -0.02          -21            2           24            -6
## 6        -0.02          -21            4           21             0
## 7        -0.02          -22            3           21            -4
##   magnet_belt_y magnet_belt_z roll_arm pitch_arm yaw_arm total_accel_arm
## 2           608          -311     -128      22.5    -161              34
## 3           600          -305     -128      22.5    -161              34
## 4           604          -310     -128      22.1    -161              34
## 5           600          -302     -128      22.1    -161              34
## 6           603          -312     -128      22.0    -161              34
## 7           599          -311     -128      21.9    -161              34
##   gyros_arm_x gyros_arm_y gyros_arm_z accel_arm_x accel_arm_y accel_arm_z
## 2        0.02       -0.02       -0.02        -290         110        -125
## 3        0.02       -0.02       -0.02        -289         110        -126
## 4        0.02       -0.03        0.02        -289         111        -123
## 5        0.00       -0.03        0.00        -289         111        -123
## 6        0.02       -0.03        0.00        -289         111        -122
## 7        0.00       -0.03        0.00        -289         111        -125
##   magnet_arm_x magnet_arm_y magnet_arm_z roll_dumbbell pitch_dumbbell
## 2         -369          337          513      13.13074      -70.63751
## 3         -368          344          513      12.85075      -70.27812
## 4         -372          344          512      13.43120      -70.39379
## 5         -374          337          506      13.37872      -70.42856
## 6         -369          342          513      13.38246      -70.81759
## 7         -373          336          509      13.12695      -70.24757
##   yaw_dumbbell total_accel_dumbbell gyros_dumbbell_x gyros_dumbbell_y
## 2    -84.71065                   37                0            -0.02
## 3    -85.14078                   37                0            -0.02
## 4    -84.87363                   37                0            -0.02
## 5    -84.85306                   37                0            -0.02
## 6    -84.46500                   37                0            -0.02
## 7    -85.09961                   37                0            -0.02
##   gyros_dumbbell_z accel_dumbbell_x accel_dumbbell_y accel_dumbbell_z
## 2             0.00             -233               47             -269
## 3             0.00             -232               46             -270
## 4            -0.02             -232               48             -269
```

```
## 5           0.00          -233             48            -270
## 6           0.00          -234             48            -269
## 7           0.00          -232             47            -270
##   magnet_dumbbell_x magnet_dumbbell_y magnet_dumbbell_z roll_forearm
## 2              -555               296               -64         28.3
## 3              -561               298               -63         28.3
## 4              -552               303               -60         28.1
## 5              -554               292               -68         28.0
## 6              -558               294               -66         27.9
## 7              -551               295               -70         27.9
##   pitch_forearm yaw_forearm total_accel_forearm gyros_forearm_x
## 2         -63.9        -153                  36            0.02
## 3         -63.9        -152                  36            0.03
## 4         -63.9        -152                  36            0.02
## 5         -63.9        -152                  36            0.02
## 6         -63.9        -152                  36            0.02
## 7         -63.9        -152                  36            0.02
##   gyros_forearm_y gyros_forearm_z accel_forearm_x accel_forearm_y
## 2            0.00           -0.02             192             203
## 3           -0.02            0.00             196             204
## 4           -0.02            0.00             189             206
## 5            0.00           -0.02             189             206
## 6           -0.02           -0.03             193             203
## 7            0.00           -0.02             195             205
##   accel_forearm_z magnet_forearm_x magnet_forearm_y magnet_forearm_z
## 2            -216              -18              661              473
## 3            -213              -18              658              469
## 4            -214              -16              658              469
## 5            -214              -17              655              473
## 6            -215               -9              660              478
## 7            -215              -18              659              470
##   classe
## 2      A
## 3      A
## 4      A
## 5      A
## 6      A
## 7      A
```

```
head(subTesting)
```

```
##    roll_belt pitch_belt yaw_belt total_accel_belt gyros_belt_x
## 1       1.41       8.07    -94.4                3         0.00
## 21      1.60       8.10    -94.4                3         0.02
## 22      1.57       8.09    -94.4                3         0.02
## 23      1.56       8.10    -94.3                3         0.02
## 25      1.53       8.11    -94.4                3         0.03
## 26      1.55       8.09    -94.4                3         0.02
##    gyros_belt_y gyros_belt_z accel_belt_x accel_belt_y accel_belt_z
## 1          0.00        -0.02          -21            4           22
```

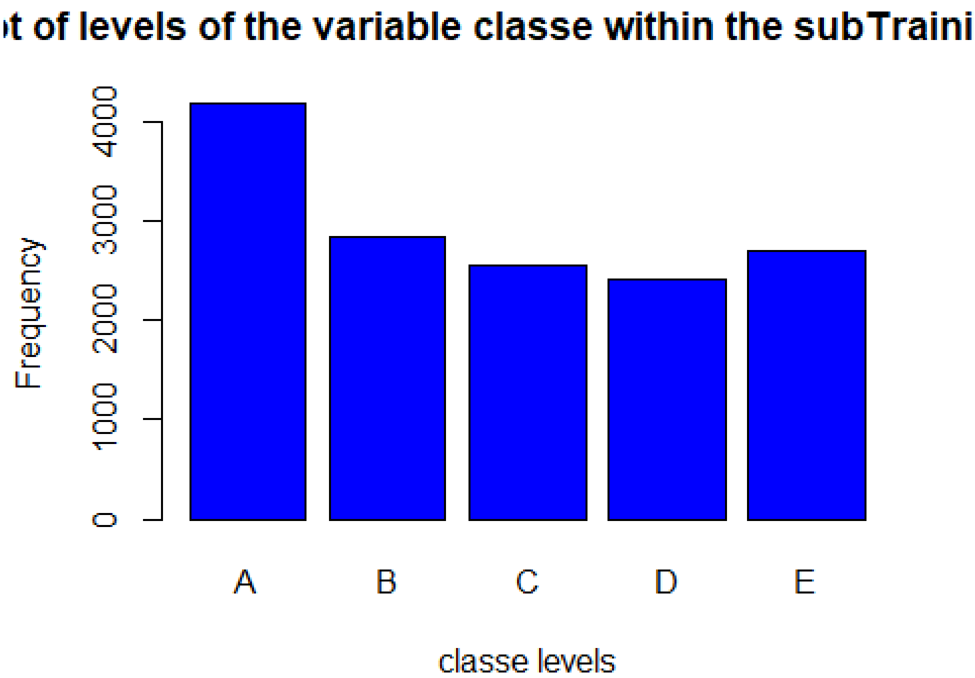
```
## 21         0.00        -0.02          -20            1           20
## 22         0.02        -0.02          -21            3           21
## 23         0.00        -0.02          -21            4           21
## 25         0.00         0.00          -19            4           21
## 26         0.00         0.00          -21            3           22
##    magnet_belt_x magnet_belt_y magnet_belt_z roll_arm pitch_arm yaw_arm
## 1             -3           599          -313     -128      22.5    -161
## 21           -10           607          -304     -129      20.9    -161
## 22            -2           604          -313     -129      20.8    -161
## 23            -4           606          -311     -129      20.7    -161
## 25            -8           605          -319     -129      20.7    -161
## 26           -10           601          -312     -129      20.7    -161
##    total_accel_arm gyros_arm_x gyros_arm_y gyros_arm_z accel_arm_x
## 1               34        0.00        0.00       -0.02        -288
## 21              34        0.03       -0.02       -0.02        -288
## 22              34        0.03       -0.02       -0.02        -289
## 23              34        0.02       -0.02       -0.02        -290
## 25              34       -0.02       -0.02        0.00        -289
## 26              34       -0.02       -0.02       -0.02        -290
##    accel_arm_y accel_arm_z magnet_arm_x magnet_arm_y magnet_arm_z
## 1          109        -123         -368          337          516
## 21         111        -124         -375          337          513
## 22         111        -123         -372          338          510
## 23         110        -123         -373          333          509
## 25         109        -123         -370          340          512
## 26         108        -123         -366          346          511
##    roll_dumbbell pitch_dumbbell yaw_dumbbell total_accel_dumbbell
## 1       13.05217      -70.49400    -84.87394                   37
## 21      13.38246      -70.81759    -84.46500                   37
## 22      13.37872      -70.42856    -84.85306                   37
## 23      13.35451      -70.63995    -84.64919                   37
## 25      13.05217      -70.49400    -84.87394                   37
## 26      12.80060      -70.31305    -85.11886                   37
##    gyros_dumbbell_x gyros_dumbbell_y gyros_dumbbell_z accel_dumbbell_x
## 1                 0            -0.02             0.00             -234
## 21                0            -0.02             0.00             -234
## 22                0            -0.02             0.00             -233
## 23                0            -0.02             0.00             -234
## 25                0            -0.02             0.00             -234
## 26                0            -0.02            -0.02             -233
##    accel_dumbbell_y accel_dumbbell_z magnet_dumbbell_x magnet_dumbbell_y
## 1                47             -271              -559               293
## 21               48             -269              -554               299
## 22               48             -270              -554               301
## 23               48             -270              -557               294
## 25               47             -271              -555               290
## 26               46             -271              -563               294
##    magnet_dumbbell_z roll_forearm pitch_forearm yaw_forearm
## 1                -65         28.4         -63.9        -153
## 21               -72         26.9         -63.9        -151
```

```
## 22                -65         27.0         -63.9        -151
## 23                -69         26.9         -63.8        -151
## 25                -68         27.1         -63.7        -151
## 26                -72         27.0         -63.7        -151
##    total_accel_forearm gyros_forearm_x gyros_forearm_y gyros_forearm_z
## 1                   36            0.03            0.00           -0.02
## 21                  36            0.03           -0.03           -0.02
## 22                  36            0.02           -0.03           -0.02
## 23                  36            0.02           -0.02           -0.02
## 25                  36            0.05           -0.03            0.00
## 26                  36            0.03            0.00            0.00
##    accel_forearm_x accel_forearm_y accel_forearm_z magnet_forearm_x
## 1              192             203            -215              -17
## 21             194             208            -214              -11
## 22             191             206            -213              -17
## 23             194             206            -214              -10
## 25             191             202            -214              -14
## 26             190             203            -216              -16
##    magnet_forearm_y magnet_forearm_z classe
## 1               654              476      A
## 21              654              469      A
## 22              654              478      A
## 23              653              467      A
## 25              667              470      A
## 26              658              462      A
```

A look at the Data

The variable "classe" contains 5 levels: A, B, C, D and E. A plot of the outcome variable will allow us to see the frequency of each levels in the subTraining data set and compare one another.

```
plot(subTraining$classe, col="blue", main="Bar Plot of levels of the variable
classe within the subTraining data set", xlab="classe levels",
ylab="Frequency")
```



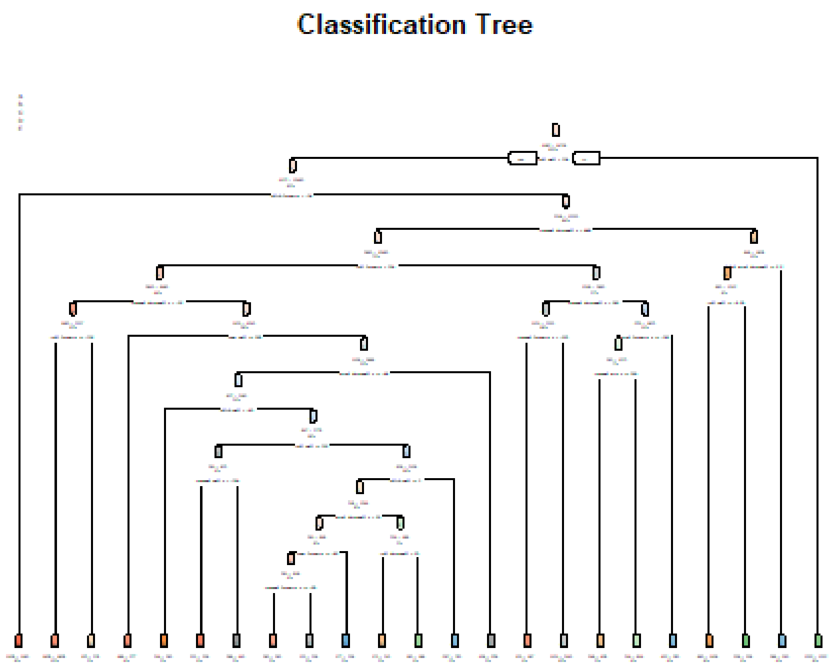
From the graph above, we can see that each level frequency is within the same order of magnitude of each other. Level A is the most frequent with more than 4000 occurrences while level D is the least frequent with about 2500 occurrences.

First prediction model: Using Decision Tree

```
model1 <- rpart(classe ~ ., data=subTraining, method="class")
# Predicting:
prediction1 <- predict(model1, subTesting, type = "class")

# Plot of the Decision Tree
rpart.plot(model1, main="Classification Tree", extra=102, under=TRUE,
faclen=0)

## Warning: labs do not fit even at cex 0.15, there may be some overplotting
```




```
##Test results on our subTesting data set
confusionMatrix(prediction1, subTesting$classe)

## Confusion Matrix and Statistics
##
##           Reference
## Prediction    A    B    C    D    E
##          A 1235  157   16   50   20
##          B   55  568   73   80  102
##          C   44  125  690  118  116
##          D   41   64   50  508   38
##          E   20   35   26   48  625
##
## Overall Statistics
##
##                Accuracy : 0.7394
##                  95% CI : (0.7269, 0.7516)
##     No Information Rate : 0.2845
##     P-Value [Acc > NIR] : < 2.2e-16
##
##                   Kappa : 0.6697
##  Mcnemar's Test P-Value : < 2.2e-16
##
## Statistics by Class:
##
##                      Class: A Class: B Class: C Class: D Class: E
## Sensitivity            0.8853   0.5985   0.8070   0.6318   0.6937
```

```
## Specificity            0.9307   0.9216   0.9005   0.9529   0.9678
## Pos Pred Value         0.8356   0.6469   0.6313   0.7247   0.8289
## Neg Pred Value         0.9533   0.9054   0.9567   0.9296   0.9335
## Prevalence             0.2845   0.1935   0.1743   0.1639   0.1837
## Detection Rate         0.2518   0.1158   0.1407   0.1036   0.1274
## Detection Prevalence   0.3014   0.1790   0.2229   0.1429   0.1538
## Balanced Accuracy      0.9080   0.7601   0.8537   0.7924   0.8307
```

Second prediction model: Using Random Forest

```
model2 <- randomForest(classe ~. , data=subTraining, method="class")

# Predicting:
prediction2 <- predict(model2, subTesting, type = "class")

# Test results on subTesting data set:
confusionMatrix(prediction2, subTesting$classe)

## Confusion Matrix and Statistics
##
##           Reference
## Prediction    A    B    C    D    E
##          A 1394    3    0    0    0
##          B    1  944   10    0    0
##          C    0    2  843    6    0
##          D    0    0    2  798    0
##          E    0    0    0    0  901
##
## Overall Statistics
##
##                Accuracy : 0.9951
##                  95% CI : (0.9927, 0.9969)
##     No Information Rate : 0.2845
##     P-Value [Acc > NIR] : < 2.2e-16
##
##                   Kappa : 0.9938
##  Mcnemar's Test P-Value : NA
##
## Statistics by Class:
##
##                      Class: A Class: B Class: C Class: D Class: E
## Sensitivity            0.9993   0.9947   0.9860   0.9925   1.0000
## Specificity            0.9991   0.9972   0.9980   0.9995   1.0000
## Pos Pred Value         0.9979   0.9885   0.9906   0.9975   1.0000
## Neg Pred Value         0.9997   0.9987   0.9970   0.9985   1.0000
## Prevalence             0.2845   0.1935   0.1743   0.1639   0.1837
## Detection Rate         0.2843   0.1925   0.1719   0.1627   0.1837
## Detection Prevalence   0.2849   0.1947   0.1735   0.1631   0.1837
## Balanced Accuracy      0.9992   0.9960   0.9920   0.9960   1.0000
```

Decision

As expected, Random Forest algorithm performed better than Decision Trees.

Accuracy for Random Forest model was 0.995 (95% CI: (0.993, 0.997)) compared to 0.739 (95% CI: (0.727, 0.752)) for Decision Tree model. The random Forest model is choosen. The accuracy of the model is 0.995. The expected out-of-sample error is estimated at 0.005, or 0.5%. The expected out-of-sample error is calculated as 1 - accuracy for predictions made against the cross-validation set. Our Test data set comprises 20 cases. With an accuracy above 99% on our cross-validation data, we can expect that very few, or none, of the test samples will be missclassified.

Submission

```
# predict outcome levels on the original Testing data set using Random Forest algorithm
predictfinal <- predict(model2, testingset, type="class")
predictfinal

##  1  2  3  4  5  6  7  8  9 10 11 12 13 14 15 16 17 18 19 20
##  B  A  B  A  A  E  D  B  A  A  B  C  B  A  E  E  A  B  B  B
## Levels: A B C D E

# Write files for submission
pml_write_files = function(x){
  n = length(x)
  path <- "C:/Santosh Working Main Folder/Data Science Course"
  for(i in 1:n){
    filename = paste0("problem_id_",i,".txt")

write.table(x[i],file=file.path(path,filename),quote=FALSE,row.names=FALSE,col.names=FALSE)
  }
}

pml_write_files(predictfinal)
```