



# transdim: Machine Learning for Transportation Data Imputation and Prediction

Reproducible Research Workshop
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#### Open-source & reproducible research:

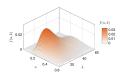
- GitHub: https://github.com/xinychen
- 2 Slides: https://xinychen.github.io/slides/transdim.pdf

#### ML algorithms



transdim
(1.1k stars)

#### Visualization tools



# Storytelling with Data

• Uber (hourly) movement speed data



NYC movement



Seattle movement

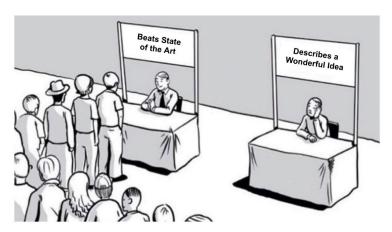
- {road segment, time step (hour), average speed}
- ullet  $Y \in \mathbb{R}^{N imes T}$  with N spatial locations imes T time steps
- Computing hourly speed: Road segments have 5+ unique trips.

Issue: Insufficient sampling of ridesharing vehicles on the road network!

# Storytelling with Data

- Data
- Quality
- Sparsity
- Estimation
- Imputation
- Interpolation
- Forecasting

# Storytelling with Data



Source: Twitter

# **Traffic Data Processing**

Computing with numpy (numerical computing in Python)

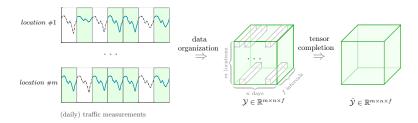
- Data format: .npz (compressed format of .npy)
- Example
- Easy to connect with numpy (in CPU environment) & cupy (in GPU environment)

## **Reformulate Traffic Data Imputation**

• Represent traffic data as tensors

Tensorization: 
$$Y \in \mathbb{R}^{m \times t} \to \mathcal{Y} \in \mathbb{R}^{m \times n \times f}$$

w/m locations, n days, and f time intervals per day.



• Tensor completion (Observed index set  $\Omega$ )

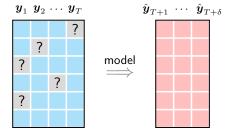


# **Reformulate Traffic Forecasting**

#### Forecasting urban traffic states with sparse data

• Problem definition ( $\delta$ -step ahead forecasting)

$$\underbrace{\{ \boldsymbol{y}_1, \boldsymbol{y}_2, \dots, \boldsymbol{y}_T \}}_{\text{Current traffic states}} \quad \underbrace{\{ \hat{\boldsymbol{y}}_{T+1}, \hat{\boldsymbol{y}}_{T+2}, \dots, \hat{\boldsymbol{y}}_{T+\delta} \}}_{\text{Future traffic states}}$$



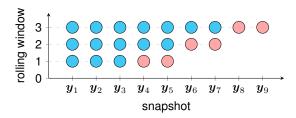
## **Reformulate Traffic Forecasting**

(Rolling) Forecasting urban traffic states with sparse data

1st rolling step:  $\{oldsymbol{y}_1, oldsymbol{y}_2, oldsymbol{y}_3\} 
ightarrow \{oldsymbol{y}_4, oldsymbol{y}_5\}$ 

2nd rolling step:  $\{{m y}_1,{m y}_2,{m y}_3,{m y}_4,{m y}_5\} o \{{m y}_6,{m y}_7\}$ 

3rd rolling step:  $\{{m y}_1,{m y}_2,{m y}_3,{m y}_4,{m y}_5,{m y}_6,{m y}_7\} o \{{m y}_8,{m y}_9\}$ 



# **TMF**

 $\mathsf{TMF}^{1,2}$ Jupyter Notebook

<sup>&</sup>lt;sup>1</sup>tracebase: <sup>2</sup>tpami

#### Switch from CPU to GPU

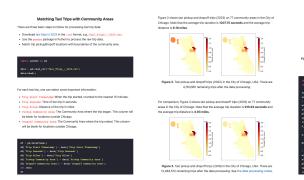
Python implementation of algorithms with the numpy package (Using less packages can improve the reproducibility) Easy to convert the codes from CPU to GPU

import numpy as np  $\Rightarrow$  import cupy as np

### **Post Something That Matters**

Post well-documented data processing files (e.g., processing Chicago taxi data)

- Beginners to build coding skills
- Researchers to build research ideas





Source: https://spatiotemporal-data.github.io/Chicago-mobility/taxi-data

# **Post Something That Matters**

#### Post scientific data modeling problems

# Optimizing Interpretable Time-Varying Autoregression with Orthogonal Constraints

Generally speaking, any spatiolemporal data in the form of a matrix can be written as  $Y \in \mathbb{R}^{N \times T}$  with N spatial areas/locations and T time steps. To discover interpretable spatial/temporal patterns, one can build a time-varying autoregression on the time snapshost  $y_1, y_2, \ldots, y_T \in \mathbb{R}^N$  (Chen et al., 2023). The time-varying coefficients in the autoregression allow one to characterize the time-varying system behavior, but the challenges still remain.

To capture interpretable modes/patterns, one can use tensor factorization formulas to parameterize the coefficients and the optimization problem can be easily built. However, a great challenge would be how to make the modes "more interpretable", specifically, e.g., how to learn orthogonal modes in the modeling process. In this post, we present an optimization problem of the time-varying autoregression with orthogonal constraints as follows.

$$\begin{aligned} \min_{\boldsymbol{W},\boldsymbol{G},\boldsymbol{V},\boldsymbol{X}} & \frac{1}{2} \sum_{t=2}^{T} \left\| \boldsymbol{y}_{t} - \boldsymbol{W} \boldsymbol{G}(\boldsymbol{x}_{t}^{\top} \otimes \boldsymbol{V})^{\top} \boldsymbol{y}_{t-1} \right\|_{2}^{2} \\ \text{s.t.} & \begin{cases} \boldsymbol{W}^{\top} \boldsymbol{W} = \boldsymbol{I}_{R} \\ \boldsymbol{V}^{\top} \boldsymbol{V} = \boldsymbol{I}_{R} \\ \boldsymbol{X}^{\top} \boldsymbol{X} = \boldsymbol{I}_{B} \end{cases} \end{aligned}$$

where  $W \in \mathbb{R}^{N \times R}$  and  $X \in \mathbb{R}^{(T-1) \times R}$  refer to as the spatial modes and the temporal modes, respectively. This model can discover urban mobility transition patterns.

Source: https://spatiotemporal-data.github.io/probs/orth-var

# Why?

#### Academic:

- Sustainable research environment (w.r.t. us & followers)
- Interact with researchers from different fields
- Provide platform and benchmark for comparison
- Stimulate new algorithmic ideas

#### Industry:

Solution to ...

#### Next-step plan:

 Spatiotemporal data modeling: https://spatiotemporal-data.github.io





# Thanks for your attention!

Any Questions?

#### About me:

★ Homepage: https://xinychen.github.io

GitHub: https://github.com/xinychen