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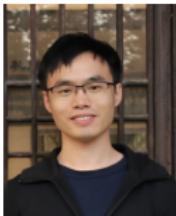
Matrix and Tensor Models for Spatiotemporal Traffic Data Imputation and Forecasting

Ph.D. Defense

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Outline

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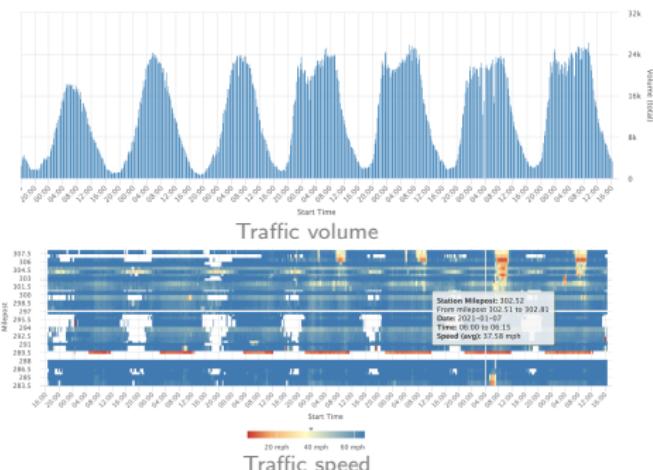
Multivariate Traffic Time Series

Many spatiotemporal traffic time series data are in the form of **matrix**.

- Example: Portland highway traffic data¹.



Highway network & sensor locations



- $X \in \mathbb{R}^{N \times T}$ with N spatial locations \times T time steps
- Traffic volume/speed shows strong spatial/temporal dependencies

¹<https://portal.its.pdx.edu/home>

Multiple Data Behaviors

Spatiotemporal traffic data are time series, but they involve multiple data behaviors.

- Incompleteness & sparsity
- High-dimensionality
- Multidimensionality
- Noises & outliers
- Time-varying behavior
- Nonstationarity
-

In addition, spatiotemporal correlations are also very important.

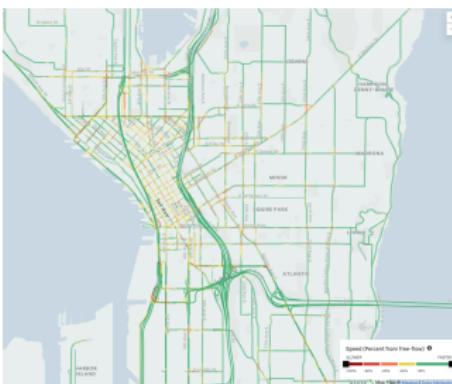
Multiple Data Behaviors

Sparsity & high-dimensionality

- Uber (hourly) movement speed data²



NYC movement



Seattle movement

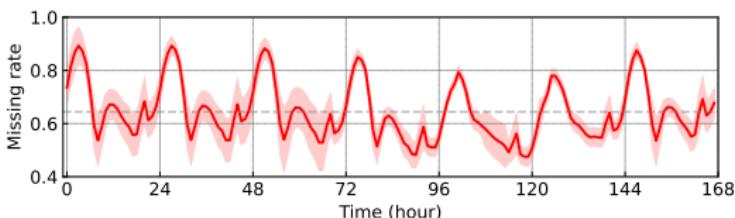
- The average speed on a given road segment for each hour of each day.
- Hourly speeds are computed when road segments have 5+ unique trips.
- **Issue:** insufficient sampling of ridesharing vehicles on the road network.

²<https://movement.uber.com/>

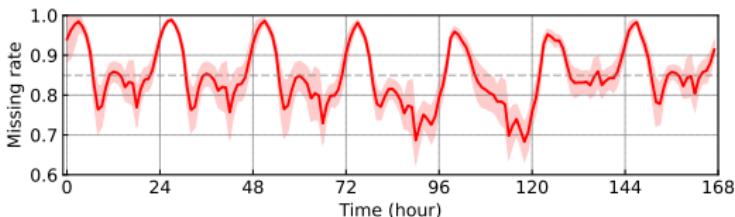
Multiple Data Behaviors

Sparsity & high-dimensionality

- **NYC** movement speed data (2019)
 - 98,210 road segments & 8,760 time steps (hours)
 - Overall missing rate: 64.43%

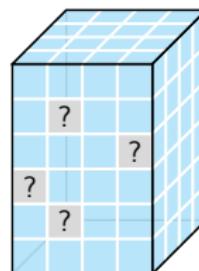
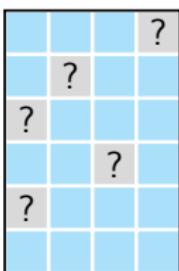


- **Seattle** movement speed data (2019)
 - 63,490 road segments & 8,760 time steps (hours)
 - Overall missing rate: 84.95%



Problem Formulation

- **Objective A:** Given a multivariate time series data like $\mathbf{Y} \in \mathbb{R}^{N \times T}$ or a multidimensional time series data like $\mathcal{Y} \in \mathbb{R}^{M \times N \times T}$ with the observed index set Ω , impute the missing values of the data.

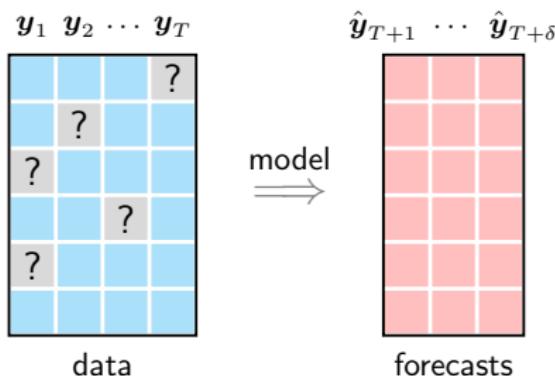


[Q]

- How to reconstruct missing values from observed data?
 - Matrix completion: From $\mathcal{P}_\Omega(\mathbf{Y})$ (observed) to $\mathcal{P}_\Omega^\perp(\mathbf{Y})$ (unobserved)
 - Tensor completion: From $\mathcal{P}_\Omega(\mathcal{Y})$ (observed) to $\mathcal{P}_\Omega^\perp(\mathcal{Y})$ (unobserved)
- How to make use of spatiotemporal correlations?
- How to make use of traffic time series dynamics?

Problem Formulation

- **Objective B:** Given a partially observed data $\mathbf{Y} \in \mathbb{R}^{N \times T}$ consisting of time series $\mathbf{y}_1, \dots, \mathbf{y}_T \in \mathbb{R}^N$, forecast data points $\hat{\mathbf{y}}_{T+\delta}, \delta \in \mathbb{N}^+$.

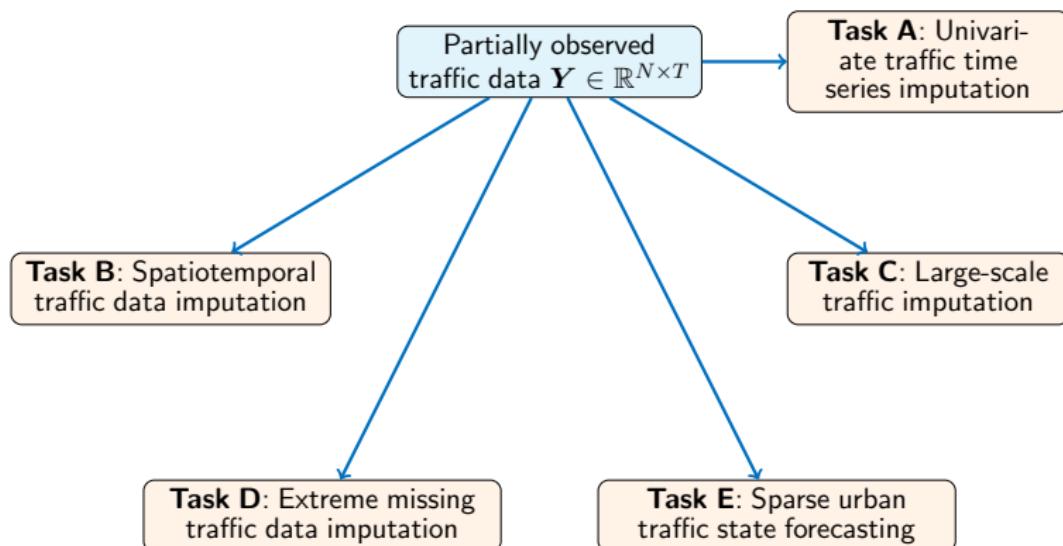


[Q]

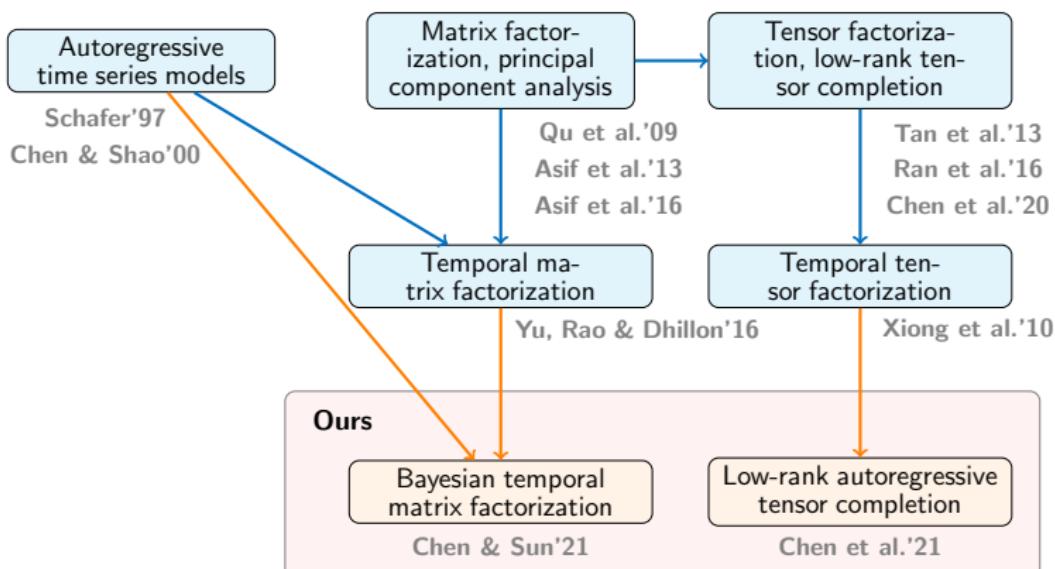
- How to learn from *high-dimensional* and *sparse* data?
- How to model *nonstationarity* in time series?
- How to perform forecasting on these time series?

Whole Picture

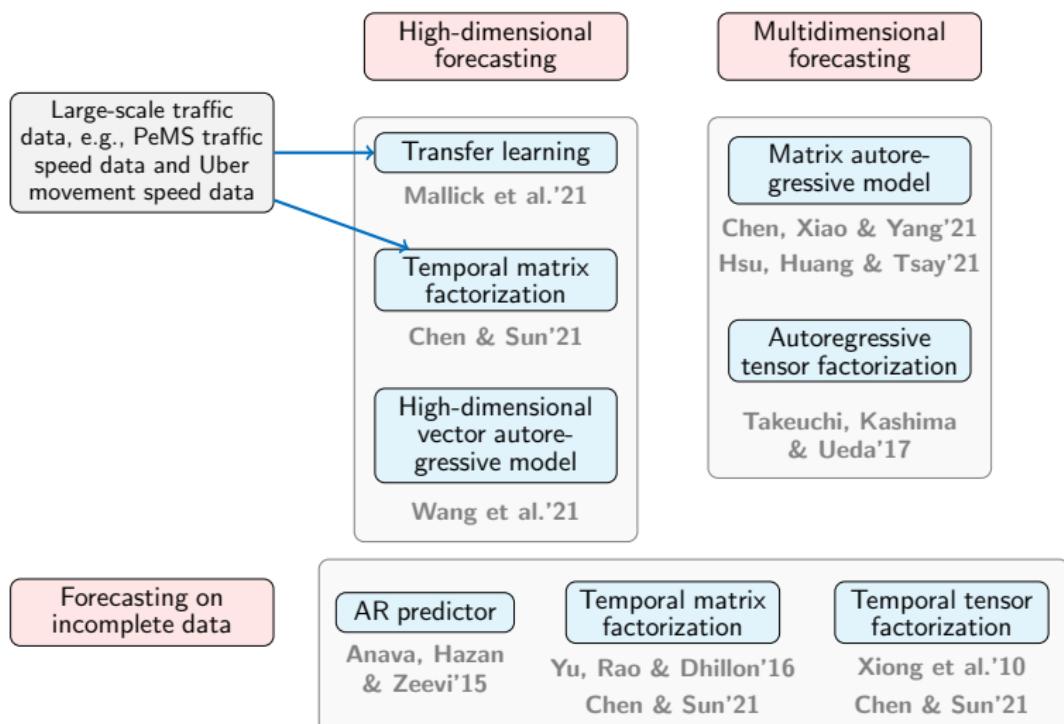
We are working on **spatiotemporal traffic data modeling**.



Spatiotemporal Traffic Data Imputation



Spatiotemporal Traffic Forecasting



Low-Rank Tensor Models

- Low-rank matrix/tensor completion



Candès & Recht'09: Convex nuclear norm minimization for matrix completion.

$$\begin{aligned} \min_{\mathbf{X}} \quad & \|\mathbf{X}\|_* \\ \text{s.t. } & \mathcal{P}_\Omega(\mathbf{X}) = \mathcal{P}_\Omega(\mathbf{Y}) \end{aligned}$$



Cai, Candès & Shen'10: Singular value thresholding algorithm.

$$\begin{cases} \mathbf{X}^\ell = \mathcal{D}_\tau(\mathbf{Z}^{\ell-1}) \\ \mathbf{Z}^\ell = \mathbf{Z}^{\ell-1} + \delta_\ell \mathcal{P}_\Omega(\mathbf{Y} - \mathbf{X}^\ell) \end{cases}$$



Zhang et al.'12: Nonconvex truncated nuclear norm minimization.



Liu et al.'13: Convex nuclear norm minimization for tensor completion.

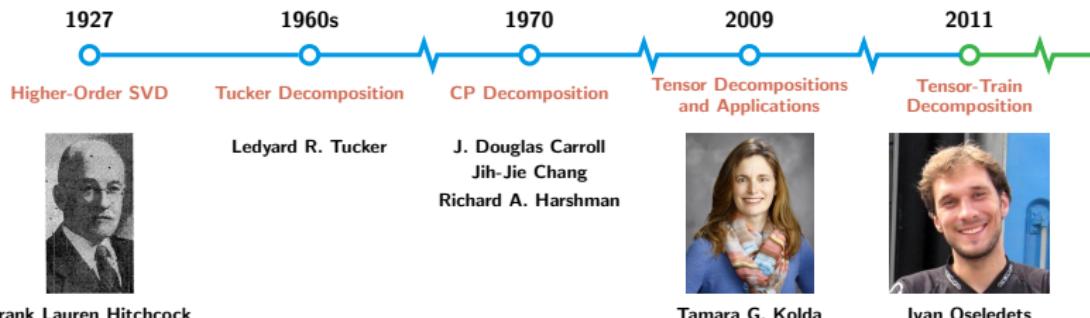
$$\begin{aligned} \min_{\boldsymbol{\mathcal{X}}} \quad & \|\boldsymbol{\mathcal{X}}\|_* \\ \text{s.t. } & \mathcal{P}_\Omega(\boldsymbol{\mathcal{X}}) = \mathcal{P}_\Omega(\mathbf{Y}) \end{aligned}$$



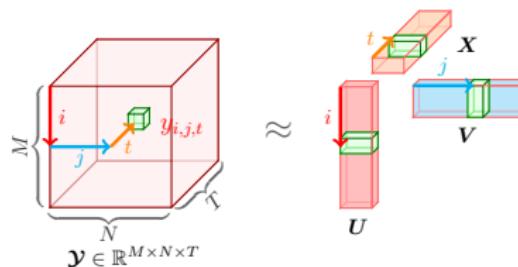
Lu, Peng & Wei'19: Tensor nuclear norm induced by linear transform.

Tensor Factorization

- Revisit tensor factorization (TF)



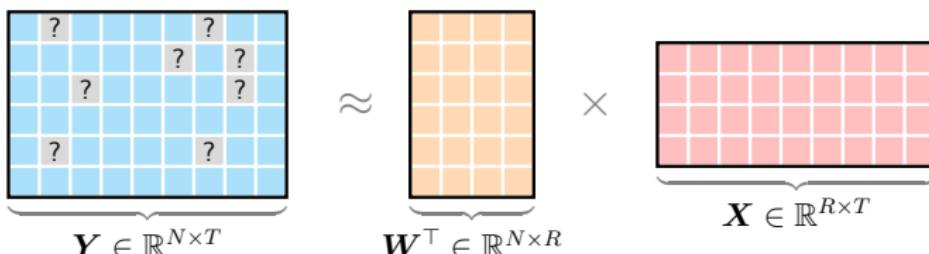
- **CP tensor factorization:** Factorize \mathcal{Y} into the combination of three rank- R factor matrices (i.e., low-dimensional latent factors).



$$\begin{cases} y_{i,j,t} \approx \sum_{r=1}^R u_{i,r} v_{j,r} x_{t,r} \\ \mathcal{Y} \approx \sum_{r=1}^R \mathbf{u}_r \otimes \mathbf{v}_r \otimes \mathbf{x}_r \end{cases}$$

Matrix Factorization

A simple approach to reconstruct missing values.



MF (Koren et al.'09)

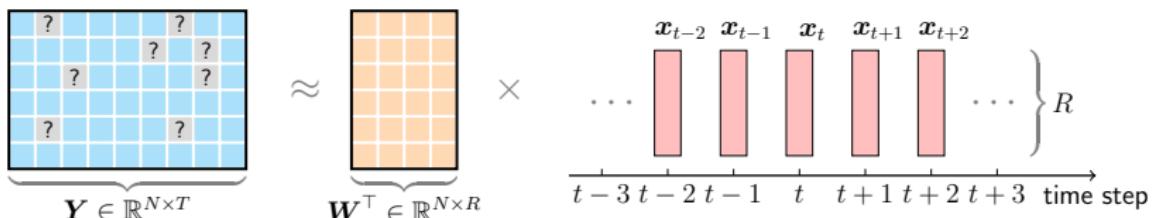
Estimating low-dimensional \mathbf{W}, \mathbf{X} :

$$\min_{\mathbf{W}, \mathbf{X}} \frac{1}{2} \|\mathcal{P}_\Omega(\mathbf{Y} - \mathbf{W}^\top \mathbf{X})\|_F^2$$

- ✓ Learn from sparse data
- ✗ Temporal correlations
- ✗ Time series forecasting

Temporal Matrix Factorization

Vector autoregression on the temporal factor matrix.



MF (Koren et al.'09)

Estimating low-dimensional \mathbf{W}, \mathbf{X} :

$$\min_{\mathbf{W}, \mathbf{X}} \frac{1}{2} \|\mathcal{P}_\Omega(\mathbf{Y} - \mathbf{W}^\top \mathbf{X})\|_F^2$$

dth-order VAR

$$\boldsymbol{x}_t = \sum_{k=1}^d \boldsymbol{A}_k \boldsymbol{x}_{t-k} + \boldsymbol{\epsilon}_t$$

w/ coefficients $\{A_k\}$.

- Temporal matrix factorization (Yu et al.'16; Chen & Sun'21)

$$\min_{\boldsymbol{W}, \boldsymbol{X}, \{\boldsymbol{A}_k\}_{k=1}^d} \frac{1}{2} \|\mathcal{P}_\Omega(\boldsymbol{Y} - \boldsymbol{W}^\top \boldsymbol{X})\|_F^2 + \frac{\gamma}{2} \sum_{t=d+1}^T \left\| \boldsymbol{x}_t - \sum_{k=1}^d \boldsymbol{A}_k \boldsymbol{x}_{t-k} \right\|_2^2$$

Nonstationary Temporal Matrix Factorization

Nonstationary temporal matrix factorization (NoTMF)

Given any partially observed time series data $\mathbf{Y} \in \mathbb{R}^{N \times T}$ with observed index set Ω , then we assume a season- m differencing on the latent temporal factors:

$$\begin{aligned} \min_{\mathbf{W}, \mathbf{X}, \{\mathbf{A}_k\}_{k=1}^d} \quad & \frac{1}{2} \|\mathcal{P}_\Omega(\mathbf{Y} - \mathbf{W}^\top \mathbf{X})\|_F^2 + \frac{\rho}{2} (\|\mathbf{W}\|_F^2 + \|\mathbf{X}\|_F^2) \\ & + \frac{1}{2} \sum_{t=d+m+1}^T \left\| (\mathbf{x}_t - \mathbf{x}_{t-m}) - \sum_{k=1}^d \mathbf{A}_k (\mathbf{x}_{t-k} - \mathbf{x}_{t-m-k}) \right\|_2^2 \end{aligned}$$

- First-order differencing $\mathbf{x}'_t = \mathbf{x}_t - \mathbf{x}_{t-1}$.
 - Second-order differencing $\mathbf{x}''_t = (\mathbf{x}_t - \mathbf{x}_{t-1}) - (\mathbf{x}_{t-1} - \mathbf{x}_{t-2})$.
 - Twice-differenced series $\mathbf{x}'''_t = (\mathbf{x}_t - \mathbf{x}_{t-m}) - (\mathbf{x}_{t-1} - \mathbf{x}_{t-m-1})$.
- ✓ Stationarizing a time series with differencing can improve the prediction.³

³Stationarity and differencing: <https://otexts.com/fpp2/stationarity.html>

Nonstationary Temporal Matrix Factorization

Rewrite VAR in the form of matrix

Temporal operators

For any multivariate time series $\mathbf{X} \in \mathbb{R}^{R \times T}$ with $m, d \in \mathbb{N}^+$, if we define temporal operators as

$$\begin{aligned}\Psi_k &\triangleq \begin{bmatrix} \mathbf{0}_{(T-d-m) \times (d-k)} & -\mathbf{I}_{T-d-m} & \mathbf{0}_{(T-d-m) \times (k+m)} \end{bmatrix} \\ &+ \begin{bmatrix} \mathbf{0}_{(T-d-m) \times (d+m-k)} & \mathbf{I}_{T-d-m} & \mathbf{0}_{(T-d-m) \times k} \end{bmatrix} \\ &\in \mathbb{R}^{(T-d-m) \times T}, k = 0, 1, \dots, d\end{aligned}$$

then

$$\begin{aligned}&\sum_{t=d+m+1}^T \|(\mathbf{x}_t - \mathbf{x}_{t-m}) - \sum_{k=1}^d \mathbf{A}_k (\mathbf{x}_{t-k} - \mathbf{x}_{t-m-k})\|_2^2 \\ &\equiv \|\mathbf{X} \Psi_0^\top - \sum_{k=1}^d \mathbf{A}_k \mathbf{X} \Psi_k^\top\|_F^2 \triangleq \|\mathbf{X} \Psi_0^\top - \mathbf{A} (\mathbf{I}_d \otimes \mathbf{X}) \Psi^\top\|_F^2\end{aligned}$$

where $\mathbf{A} \triangleq [\mathbf{A}_1 \quad \cdots \quad \mathbf{A}_d]$ and $\Psi \triangleq [\Psi_1 \quad \cdots \quad \Psi_d]$.

Nonstationary Temporal Matrix Factorization

Rewrite NoTMF:

$$\begin{aligned} \min_{\mathbf{W}, \mathbf{X}, \mathbf{A}} \quad & \frac{1}{2} \|\mathcal{P}_\Omega(\mathbf{Y} - \mathbf{W}^\top \mathbf{X})\|_F^2 + \frac{\rho}{2} (\|\mathbf{W}\|_F^2 + \|\mathbf{X}\|_F^2) \\ & + \frac{\lambda}{2} \|\mathbf{X} \Psi_0^\top - \mathbf{A} (\mathbf{I}_d \otimes \mathbf{X}) \Psi^\top\|_F^2 \end{aligned}$$

Alternating minimization method:

- w.r.t. \mathbf{W} :

$$\frac{\partial f}{\partial \mathbf{W}} = -\mathbf{X} \mathcal{P}_\Omega^\top (\mathbf{Y} - \mathbf{W}^\top \mathbf{X}) + \rho \mathbf{W} = \mathbf{0}$$

- w.r.t. \mathbf{X} :

$$\frac{\partial f}{\partial \mathbf{X}} = -\mathbf{W} \mathcal{P}_\Omega (\mathbf{Y} - \mathbf{W}^\top \mathbf{X}) + \rho \mathbf{X} + \lambda \sum_{k=0}^d \mathbf{A}_k^\top \left(\sum_{h=0}^d \mathbf{A}_h \mathbf{X} \Psi_h^\top \right) \Psi_k = \mathbf{0}$$

- w.r.t. \mathbf{A} :

$$\mathbf{A} = \mathbf{X} \Psi_0^\top [(\mathbf{I}_d \otimes \mathbf{X}) \Psi^\top]^\dagger$$

Nonstationary Temporal Matrix Factorization

NoTMF forecasting on streaming data?

- NoTMF: Use \mathbf{Y}_t to estimate $\{\mathbf{W}, \mathbf{X}, \mathbf{A}\}$.

$$\underbrace{\mathbf{Y}_t}_{\in \mathbb{R}^{N \times t}} = \begin{matrix} ? & & & ? \\ & ? & & ? \\ ? & & ? & \end{matrix}$$

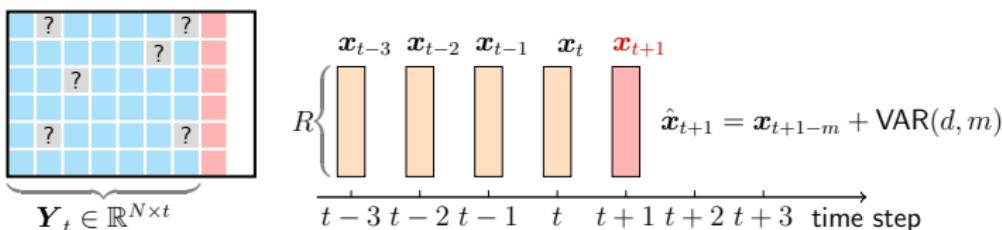
$$R \left\{ \begin{matrix} \mathbf{x}_{t-3} & \mathbf{x}_{t-2} & \mathbf{x}_{t-1} & \mathbf{x}_t & \mathbf{x}_{t+1} \\ t-3 & t-2 & t-1 & t & t+1 \end{matrix} \right. \quad \hat{\mathbf{x}}_{t+1} = \mathbf{x}_{t+1-m} + \text{VAR}(d, m)$$

time step

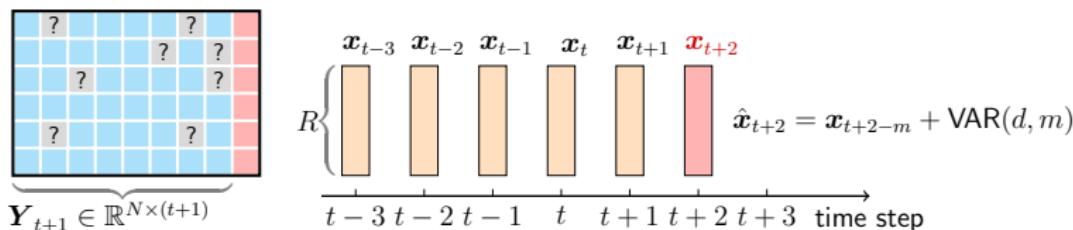
Nonstationary Temporal Matrix Factorization

NoTMF forecasting on streaming data?

- NoTMF: Use \mathbf{Y}_t to estimate $\{\mathbf{W}, \mathbf{X}, \mathbf{A}\}$.



- Online forecasting (Gultekin & Paisley'18): Fix \mathbf{W} and use \mathbf{Y}_{t+1} to update $\{\mathbf{X}, \mathbf{A}\}$.



Matrix/Tensor Completion

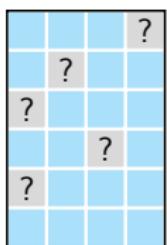
Cornerstone: Nuclear norm minimization in matrix/tensor completion

LRMC (Candès & Recht'09)

Estimating the matrix \mathbf{X} :

$$\min_{\mathbf{X}} \|\mathbf{X}\|_*$$

$$\text{s.t. } \mathcal{P}_\Omega(\mathbf{X}) = \mathcal{P}_\Omega(\mathbf{Y})$$



$$\mathcal{P}_\Omega(\mathbf{Y}) \in \mathbb{R}^{N \times T}$$

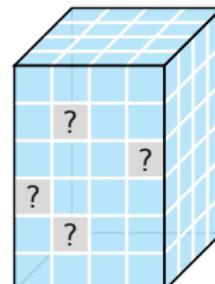
LRTC (Liu et al.'13)

Estimating the tensor \mathcal{X} :

$$\min_{\mathcal{X}} \|\mathcal{X}\|_*$$

$$\text{s.t. } \mathcal{P}_\Omega(\mathcal{X}) = \mathcal{P}_\Omega(\mathcal{Y})$$

vs.



$$\mathcal{P}_\Omega(\mathcal{Y}) \in \mathbb{R}^{N \times I \times J}$$

- **Limitation:** Only cover global consistency
- **Highlight:** Introduce local consistency (e.g., temporal correlations)

Background
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Literature Review
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NoTMF
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LATC
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LCR
oooooooo

HTF
ooooooooo

Experiments
ooooooo

Conclusion
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Low-Rank Autoregressive Tensor Completion

Low-Rank Autoregressive Tensor Completion

- Tensorization
- Autoregression

Low-Rank Autoregressive Tensor Completion

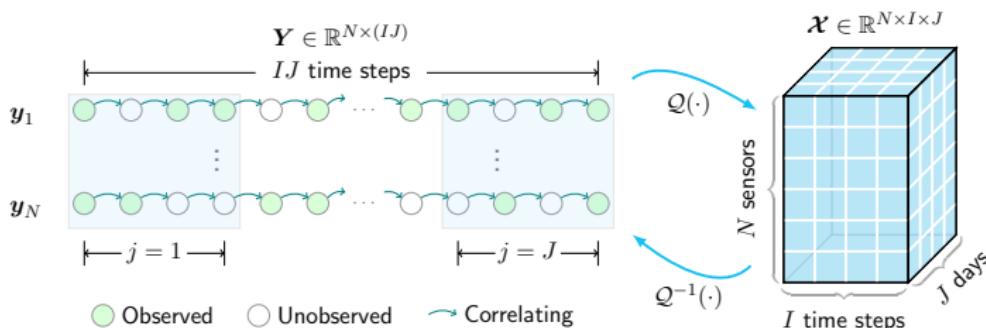
Low-Rank Autoregressive Tensor Completion (LATC)

For any partially observed traffic data $\mathbf{Y} \in \mathbb{R}^{N \times T}$ with observed index set Ω , LATC takes

$$\begin{aligned} & \min_{\mathbf{Z}, \mathbf{A}} \|\mathcal{Q}(\mathbf{Z})\|_{r,*} + \frac{\gamma}{2} \|\mathbf{Z}\|_{\mathbf{A}, \mathcal{H}} \\ & \text{s.t. } \mathcal{P}_{\Omega}(\mathbf{Z}) = \mathcal{P}_{\Omega}(\mathbf{Y}) \end{aligned}$$

Advantages:

- ✓ Global consistency (w/ tensor representation)
- ✓ Local consistency (w/ temporal autoregression)



Background
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Literature Review
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NoTMF
oooooo

LATC
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LCR
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HTF
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Experiments
ooooooo

Conclusion
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Low-Rank Autoregressive Tensor Completion

- Optimization problem:

$$\begin{aligned} \min_{\mathbf{Z}, \mathbf{A}} \quad & \|\mathcal{Q}(\mathbf{Z})\|_{r,*} + \frac{\gamma}{2} \|\mathbf{Z}\|_{\mathbf{A}, \mathcal{H}} \\ \text{s.t. } \mathcal{P}_{\Omega}(\mathbf{Z}) = \mathcal{P}_{\Omega}(\mathbf{Y}) \end{aligned}$$

- Two subproblems:

$$\begin{cases} \mathbf{Z} := \underset{\mathcal{P}_{\Omega}(\mathbf{Z})=\mathcal{P}_{\Omega}(\mathbf{Y})}{\arg \min} \|\mathcal{Q}(\mathbf{Z})\|_{r,*} + \frac{\gamma}{2} \|\mathbf{Z}\|_{\mathbf{A}, \mathcal{H}} \\ \mathbf{A} := \frac{1}{2} \|\mathbf{Z}\|_{\mathbf{A}, \mathcal{H}} \quad (\text{Least squares}) \end{cases}$$

- Optimize \mathbf{Z} ? Write down the augmented Lagrangian function:

$$\mathcal{L}(\mathbf{X}, \mathbf{Z}, \mathbf{W}) = \|\mathbf{X}\|_{r,*} + \frac{\gamma}{2} \|\mathbf{Z}\|_{\mathbf{A}, \mathcal{H}} + \frac{\lambda}{2} \|\mathbf{X} - \mathcal{Q}(\mathbf{Z})\|_F^2 + \langle \mathbf{W}, \mathbf{X} - \mathcal{Q}(\mathbf{Z}) \rangle + \pi(\mathbf{Z})$$

where $\mathbf{W} \in \mathbb{R}^{N \times I \times J}$ is the Lagrange multiplier, and $\langle \cdot, \cdot \rangle$ denotes the inner product.⁴

⁴The indicator function is $\pi(\mathbf{Z}) = \begin{cases} 0, & \text{if } \mathcal{P}_{\Omega}(\mathbf{Z}) = \mathcal{P}_{\Omega}(\mathbf{Y}), \\ +\infty, & \text{otherwise.} \end{cases}$

Low-Rank Autoregressive Tensor Completion

- Augmented Lagrangian function:

$$\mathcal{L}(\mathbf{X}, \mathbf{Z}, \mathbf{W}) = \|\mathbf{X}\|_{r,*} + \frac{\gamma}{2} \|\mathbf{Z}\|_{A,\mathcal{H}} + \frac{\lambda}{2} \|\mathbf{X} - \mathcal{Q}(\mathbf{Z})\|_F^2 + \langle \mathbf{W}, \mathbf{X} - \mathcal{Q}(\mathbf{Z}) \rangle + \pi(\mathbf{Z})$$

- The ADMM⁵ scheme:

$$\begin{cases} \mathbf{X} := \arg \min_{\mathbf{X}} \mathcal{L}(\mathbf{X}, \mathbf{Z}, \mathbf{W}) & \text{(Truncated nuclear norm minimization)} \\ \mathbf{Z} := \arg \min_{\mathbf{Z}} \mathcal{L}(\mathbf{X}, \mathbf{Z}, \mathbf{W}) & \text{(Generalized Sylvester equation)} \\ \mathbf{W} := \mathbf{W} + \lambda(\mathbf{X} - \mathcal{Q}(\mathbf{Z})) & \text{(Standard update)} \end{cases}$$

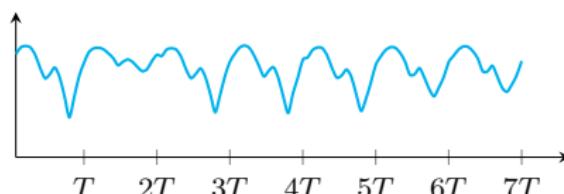
- ✓ Solution to \mathbf{X} : singular value thresholding
- ✓ Solution to \mathbf{Z} : conjugate gradient

⁵Alternating Direction Method of Multipliers.

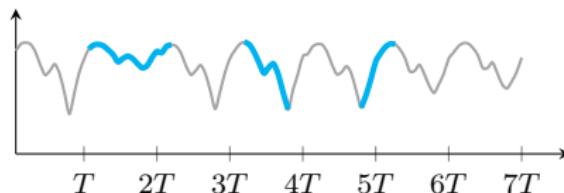
Laplacian Convolutional Representation

Motivation: Time series imputation

- Global trends (e.g., long-term quasi-seasonality & daily/weekly rhythm):



- Local trends (e.g., short-term time series trends):

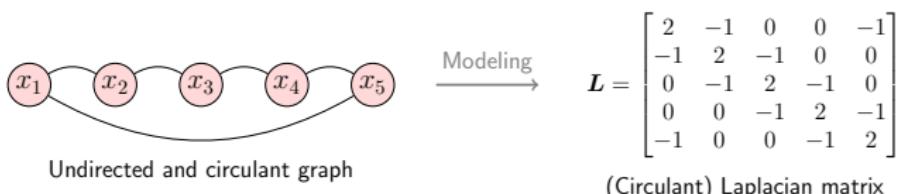


- [Question] How to characterize both global and local trends in sparse time series data?

Laplacian Convolutional Representation

[Local trend modeling] Reformulate temporal regularization with circular convolution.

- Intuition of (circulant) Laplacian matrix.



- Define Laplacian kernel:

$$\boldsymbol{\ell} \triangleq (2, -1, 0, 0, -1)^\top$$

\Downarrow

$$\boldsymbol{\ell} \triangleq (\underbrace{2\tau}_{\text{degree}}, \underbrace{-1, \dots, -1}_\tau, 0, \dots, 0, \underbrace{-1, \dots, -1}_\tau)^\top \in \mathbb{R}^T$$

for any time series $\mathbf{x} = (x_1, \dots, x_T)^\top \in \mathbb{R}^T$.

- (Laplacian) Temporal regularization:

$$\mathcal{R}_\tau(\mathbf{x}) = \frac{1}{2} \|\mathbf{L}\mathbf{x}\|_2^2 = \frac{1}{2} \|\boldsymbol{\ell} * \mathbf{x}\|_2^2$$

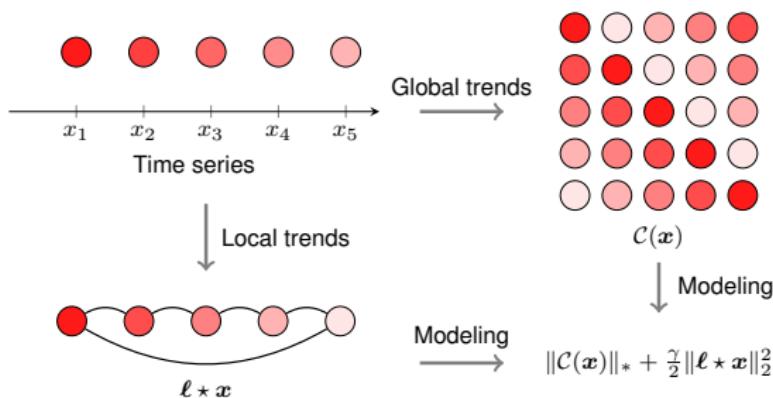
Laplacian Convolutional Representation

Laplacian Convolutional Representation (LCR)

For any partially observed time series $\mathbf{y} \in \mathbb{R}^T$ with observed index set Ω , LCR utilizes circulant matrix and Laplacian kernel to characterize **global and local trends** in time series, respectively, i.e.,

$$\begin{aligned} & \min_{\mathbf{x}} \|\mathcal{C}(\mathbf{x})\|_* + \frac{\gamma}{2} \|\ell * \mathbf{x}\|_2^2 \\ & \text{s.t. } \|\mathcal{P}_\Omega(\mathbf{x} - \mathbf{y})\|_2 \leq \epsilon \end{aligned}$$

where $\mathcal{C} : \mathbb{R}^T \rightarrow \mathbb{R}^{T \times T}$ denotes the circulant operator. $\|\cdot\|_*$ denotes the nuclear norm of matrix, namely, the sum of singular values.



Laplacian Convolutional Representation

- Augmented Lagrangian function:

$$\mathcal{L}(\mathbf{x}, \mathbf{z}, \mathbf{w}) = \|\mathcal{C}(\mathbf{x})\|_* + \frac{\gamma}{2} \|\ell * \mathbf{x}\|_2^2 + \frac{\lambda}{2} \|\mathbf{x} - \mathbf{z}\|_2^2 + \langle \mathbf{w}, \mathbf{x} - \mathbf{z} \rangle + \frac{\eta}{2} \|\mathcal{P}_\Omega(\mathbf{z} - \mathbf{y})\|_2^2$$

where $\mathbf{w} \in \mathbb{R}^T$ is the Lagrange multiplier, and $\langle \cdot, \cdot \rangle$ denotes the inner product.

- The ADMM scheme:

$$\begin{cases} \mathbf{x} := \arg \min_{\mathbf{x}} \mathcal{L}(\mathbf{x}, \mathbf{z}, \mathbf{w}) & \text{(Nuclear norm minimization)} \\ \mathbf{z} := \arg \min_{\mathbf{z}} \mathcal{L}(\mathbf{x}, \mathbf{z}, \mathbf{w}) & \text{(Closed-form solution)} \\ = \frac{1}{\lambda + \eta} \mathcal{P}_\Omega(\lambda \mathbf{x} + \mathbf{w} + \eta \mathbf{y}) + \frac{1}{\lambda} \mathcal{P}_\Omega^\perp(\lambda \mathbf{x} + \mathbf{w}) \\ \mathbf{w} := \mathbf{w} + \lambda(\mathbf{x} - \mathbf{z}) & \text{(Standard update)} \end{cases}$$

- Optimize \mathbf{x} ?

$$\|\mathcal{C}(\mathbf{x})\|_* = \|\mathcal{F}(\mathbf{x})\|_1 \quad \& \quad \frac{1}{2} \|\ell * \mathbf{x}\|_2^2 = \frac{1}{2T} \|\mathcal{F}(\ell) \circ \mathcal{F}(\mathbf{x})\|_2^2$$

Nuclear norm minimization \Rightarrow **ℓ_1 -norm minimization with FFT** (in $\mathcal{O}(T \log T)$ time).

Laplacian Convolutional Representation

- Optimize \mathbf{x} via FFT (in $\mathcal{O}(T \log T)$ time):

$$\begin{aligned}\mathbf{x} &:= \arg \min_{\mathbf{x}} \|\mathcal{C}(\mathbf{x})\|_* + \frac{\gamma}{2} \|\ell * \mathbf{x}\|_2^2 + \frac{\lambda}{2} \|\mathbf{x} - \mathbf{z} + \mathbf{w}/\lambda\|_2^2 \\ \implies \hat{\mathbf{x}} &:= \arg \min_{\hat{\mathbf{x}}} \|\hat{\mathbf{x}}\|_1 + \frac{\gamma}{2T} \|\hat{\ell} \circ \hat{\mathbf{x}}\|_2^2 + \frac{\lambda}{2T} \|\hat{\mathbf{x}} - \hat{\mathbf{z}} + \hat{\mathbf{w}}/\lambda\|_2^2\end{aligned}$$

where we introduce $\{\hat{\ell}, \hat{\mathbf{x}}, \hat{\mathbf{z}}, \hat{\mathbf{w}}\} \triangleq \mathcal{F}\{\ell, \mathbf{x}, \mathbf{z}, \mathbf{w}\}$ (i.e., FFT).

ℓ_1 -norm Minimization in Complex Space (Liu & Zhang'23)

For any optimization problem in the form of ℓ_1 -norm minimization in complex space:

$$\min_{\hat{\mathbf{x}}} \|\hat{\mathbf{x}}\|_1 + \frac{\omega}{2} \|\hat{\mathbf{x}} - \hat{\mathbf{h}}\|_2^2$$

with complex-valued vectors $\hat{\mathbf{x}}, \hat{\mathbf{h}} \in \mathbb{C}^T$ and weight parameter ω , element-wise, the solution is given by

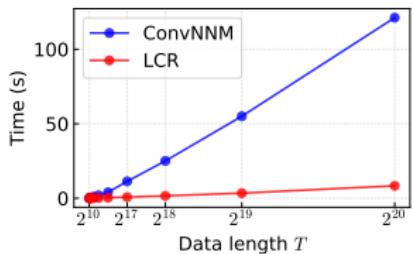
$$\hat{x}_t := \frac{\hat{h}_t}{|\hat{h}_t|} \cdot \max\{0, |\hat{h}_t| - 1/\omega\}, t = 1, \dots, T.$$

Laplacian Convolutional Representation

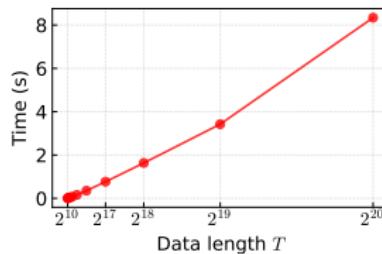
Empirical time complexity

On the synthetic data $\mathbf{y} \in \mathbb{R}^T$ with $T \in \{2^{10}, 2^{11}, \dots, 2^{20}\}$

- Ours: **LCR**
 - An FFT implementation in $\mathcal{O}(T \log T)$
 - The logarithmic factor $\log T$ makes the FFT highly efficient
- Baseline: **ConvNNM**⁶ (Liu & Zhang'23)
 - Convolution matrix $C_{\tilde{\tau}}(\mathbf{y}) \in \mathbb{R}^{T \times \tilde{\tau}}$ with kernel size $\tilde{\tau} \in \mathbb{N}^+$
 - Singular value thresholding in $\mathcal{O}(\tilde{\tau}^2 T)$



ConvNNM vs. LCR



LCR

⁶Convolution nuclear norm minimization.

Two-Dimensional LCR (LCR-2D)

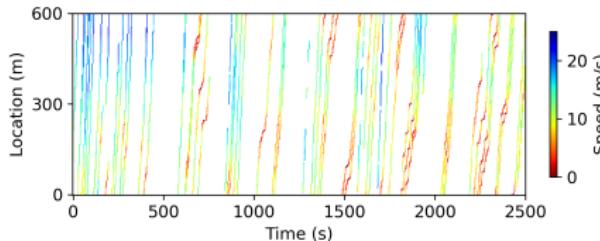
For any partially observed time series $\mathbf{Y} \in \mathbb{R}^{N \times T}$ with observed index set Ω , LCR can be formulated as follows,

$$\begin{aligned} & \min_{\mathbf{X}} \|\mathcal{C}(\mathbf{X})\|_* + \frac{\gamma}{2} \|(\boldsymbol{\ell}_s \boldsymbol{\ell}^\top) \star \mathbf{X}\|_F^2 \\ & \text{s.t. } \|\mathcal{P}_\Omega(\mathbf{X} - \mathbf{Y})\|_F \leq \epsilon \end{aligned}$$

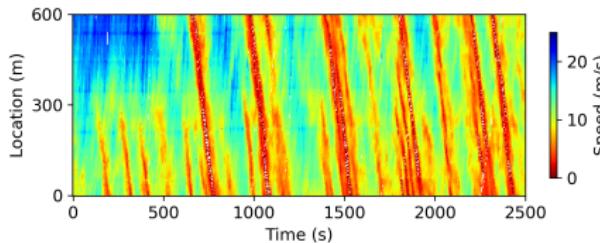
where $\mathcal{C} : \mathbb{R}^{N \times T} \rightarrow \mathbb{R}^{N \times N \times T \times T}$ denotes the circulant operator.

Motivation: Spatiotemporal data reconstruction

- Speed field reconstruction problem in vehicular traffic flow.



200-by-500 matrix
(NGSIM) \Downarrow Reconstruct speed field from
5% sparse trajectories?



- How to learn from sparse spatiotemporal data?
- How to characterize spatial/temporal dependencies?

Hankel Tensor Factorization

- Hankel matrix
 - Given $\mathbf{x} = (1, 2, 3, 4, 5)^\top$ and window length $\tau = 2$, we have

$$\mathcal{H}_\tau(\mathbf{x}) = \begin{bmatrix} 1 & 2 \\ 2 & 3 \\ 3 & 4 \\ 4 & 5 \end{bmatrix} \in \mathbb{R}^{4 \times 2}$$



Hankel matrix (Source: Twitter)

Hankel Tensor Factorization

- Hankel matrix

- On time series $\mathbf{y} = (y_1, y_2, \dots, y_5)^\top$ with $\tau = 2$:

$$\mathcal{H}_\tau(\mathbf{y}) = \begin{bmatrix} y_1 & y_2 \\ y_2 & y_3 \\ y_3 & y_4 \\ y_4 & y_5 \end{bmatrix} \approx \begin{bmatrix} v_1 \\ v_2 \\ v_3 \\ v_4 \end{bmatrix} \otimes \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$$

$$\implies \hat{\mathbf{y}} = \begin{bmatrix} \hat{y}_1 \\ \hat{y}_2 \\ \hat{y}_3 \\ \hat{y}_4 \\ \hat{y}_5 \end{bmatrix} = \mathcal{H}_\tau^{-1} \left(\begin{bmatrix} v_1 x_1 & v_1 x_2 \\ v_2 x_1 & v_2 x_2 \\ v_3 x_1 & v_3 x_2 \\ v_4 x_1 & v_4 x_2 \end{bmatrix} \right) = \begin{bmatrix} v_1 x_1 \\ (\color{blue}{v_1 x_2 + v_2 x_1})/2 \\ (\color{blue}{v_2 x_2 + v_3 x_1})/2 \\ (\color{blue}{v_3 x_2 + v_4 x_1})/2 \\ v_4 x_2 \end{bmatrix}$$

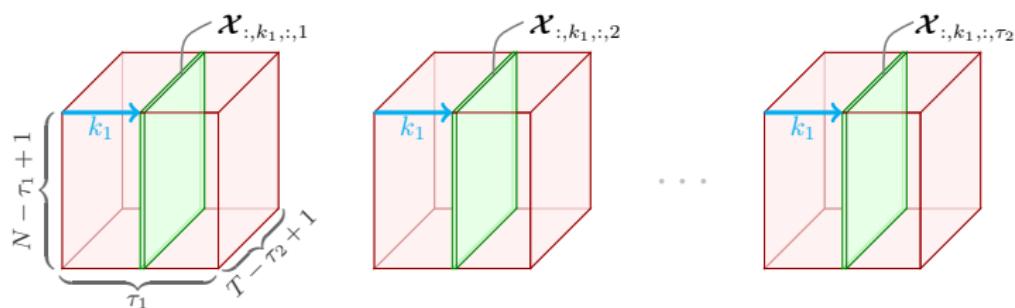
- Automatic temporal modeling.

Hankel Tensor Factorization

- Hankel tensor: Given any matrix $\mathbf{X} \in \mathbb{R}^{N \times T}$, we have

$$\mathcal{X} \triangleq \mathcal{H}_{\tau_1, \tau_2}(\mathbf{X})$$

- Window lengths: $\tau_1, \tau_2 \in \mathbb{N}^+$;
- Tensor size: $(N - \tau_1 + 1) \times \tau_1 \times (T - \tau_2 + 1) \times \tau_2$;



(Figure) 4th order Hankel tensor: A sequence of third-order tensors.

- Slice: $\mathcal{X}_{:,k_1,:,k_2}$, $\forall k_1, k_2$;
- Slice size: $(N - \tau_1 + 1) \times (T - \tau_2 + 1)$.

Hankel Tensor Factorization

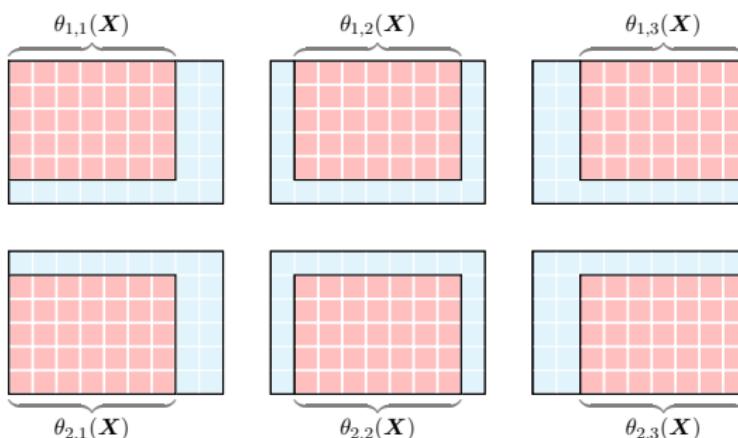
Hankel indexing:

- Sampling function for the Hankelization:

$$\theta_{k_1, k_2}(\mathbf{X}) \triangleq [\mathcal{H}_{\tau_1, \tau_2}(\mathbf{X})]_{:, k_1, :, k_2},$$

referring to the tensor slice with $k_1 \in \{1, \dots, \tau_1\}$, $k_2 \in \{1, \dots, \tau_2\}$.

- [Importance] Developing memory-efficient algorithms.



- Tensor slices $\theta_{k_1, k_2}(\mathbf{X})$ vs. data matrix \mathbf{X}

Hankel Tensor Factorization

Ours:

- Convolutional tensor decomposition (circular convolution \star_{row}):

$$\theta_{k_1, k_2}(\mathbf{Y}) \approx (\mathbf{Q} \star_{\text{row}} \mathbf{s}_{k_1}^{\top})(\mathbf{U} \star_{\text{row}} \mathbf{v}_{k_2}^{\top})^{\top}$$

Baselines:

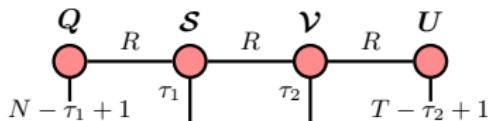
- CP tensor decomposition (Khatri-Rao product \odot):

$$\theta_{k_1, k_2}(\mathbf{Y}) \approx (\mathbf{Q} \odot \mathbf{s}_{k_1}^{\top})(\mathbf{U} \odot \mathbf{v}_{k_2}^{\top})^{\top}$$

- Tensor-train decomposition:

$$\theta_{k_1, k_2}(\mathbf{Y}) \approx (\mathbf{Q} \mathbf{S}_{k_1})(\mathbf{U} \mathbf{V}_{k_2})^{\top}$$

- $\{\mathbf{S}_{k_1}, \mathbf{V}_{k_2}\}$ are **circulant matrices** \Rightarrow convolutional decomposition
- $\{\mathbf{S}_{k_1}, \mathbf{V}_{k_2}\}$ are **diagonal matrices** \Rightarrow CP decomposition



Hankel Tensor Factorization

HTF (convolutional decomposition)

- Optimization problem:

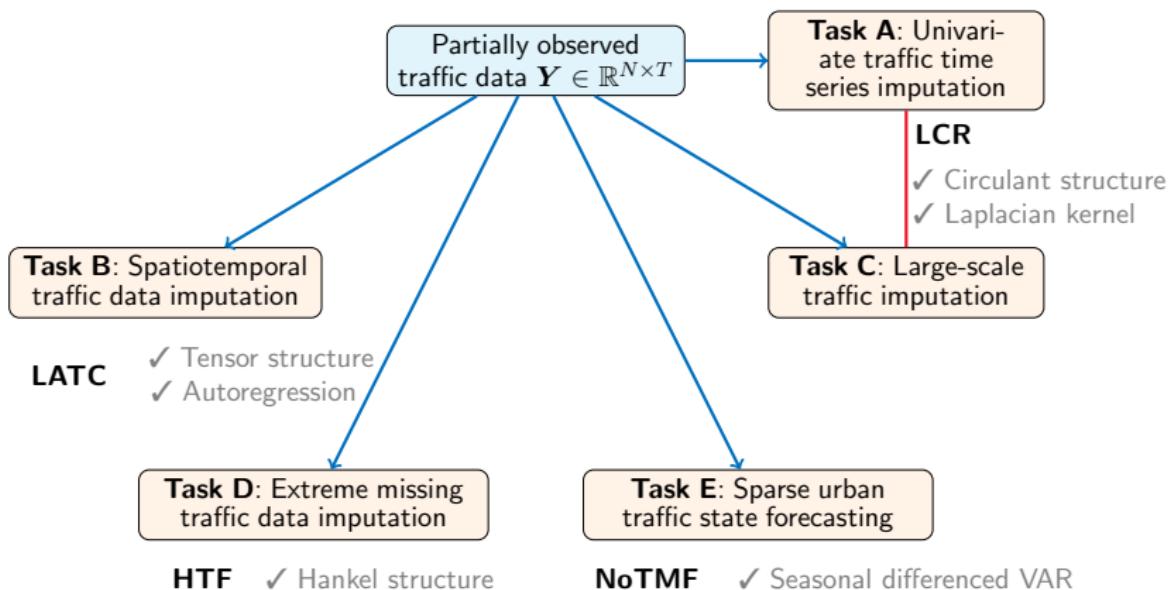
$$\begin{aligned} \min_{\mathbf{Q}, \mathbf{S}, \mathbf{U}, \mathbf{V}} \quad & \frac{1}{2} \sum_{k_1, k_2} \left\| \mathcal{P}_{\Omega_{k_1, k_2}} (\theta_{k_1, k_2}(\mathbf{Y}) - (\mathbf{Q} \star_{\text{row}} \mathbf{s}_{k_1})(\mathbf{U} \star_{\text{row}} \mathbf{v}_{k_2})^\top) \right\|_F^2 \\ & + \frac{\rho}{2} (\|\mathbf{Q}\|_F^2 + \|\mathbf{S}\|_F^2 + \|\mathbf{U}\|_F^2 + \|\mathbf{V}\|_F^2) \end{aligned}$$

- Alternating minimization:

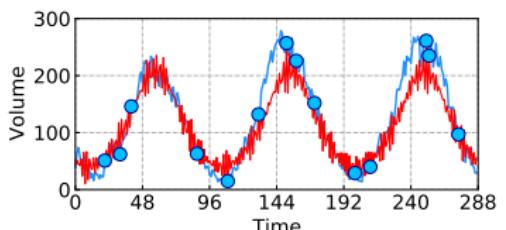
$$\left\{ \begin{array}{l} \mathbf{Q} := \{\mathbf{Q} \mid \frac{\partial f}{\partial \mathbf{Q}} = \mathbf{0}\} \\ \mathbf{s}_{k_1} := \{\mathbf{s}_{k_1} \mid \frac{\partial f}{\partial \mathbf{s}_{k_1}} = \mathbf{0}\}, k_1 \in \{1, 2, \dots, \tau_1\} \\ \mathbf{U} := \{\mathbf{U} \mid \frac{\partial f}{\partial \mathbf{U}} = \mathbf{0}\} \\ \mathbf{v}_{k_2} := \{\mathbf{v}_{k_2} \mid \frac{\partial f}{\partial \mathbf{v}_{k_2}} = \mathbf{0}\}, k_2 \in \{1, 2, \dots, \tau_2\} \end{array} \right.$$

Whole Picture

We are working on **spatiotemporal traffic data modeling**.



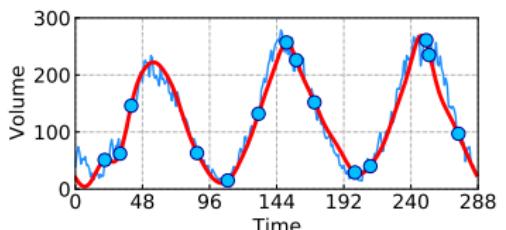
Univariate Traffic Time Series Imputation



CircNNM:

$$\begin{aligned} & \min_{\mathbf{x}} \|\mathcal{C}(\mathbf{x})\|_* \\ \text{s. t. } & \|\mathcal{P}_\Omega(\mathbf{x} - \mathbf{y})\|_2 \leq \epsilon \end{aligned}$$

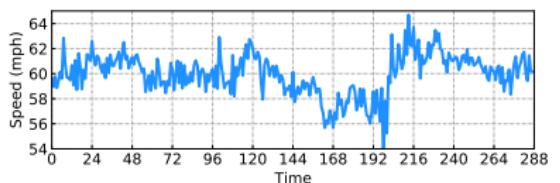
↓ Plus temporal regularization (TR)



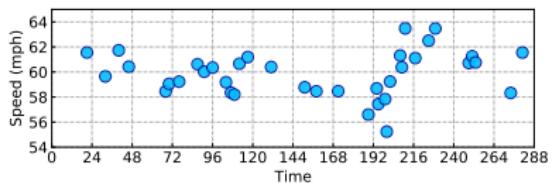
LCR:

$$\begin{aligned} & \min_{\mathbf{x}} \|\mathcal{C}(\mathbf{x})\|_* + \frac{\gamma}{2} \|\ell \star \mathbf{x}\|_2^2 \\ \text{s. t. } & \|\mathcal{P}_\Omega(\mathbf{x} - \mathbf{y})\|_2 \leq \epsilon \end{aligned}$$

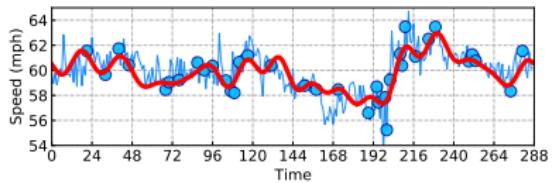
Univariate Traffic Time Series Imputation



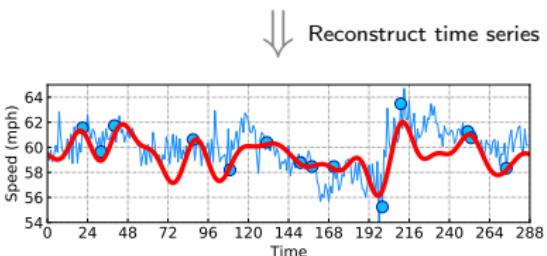
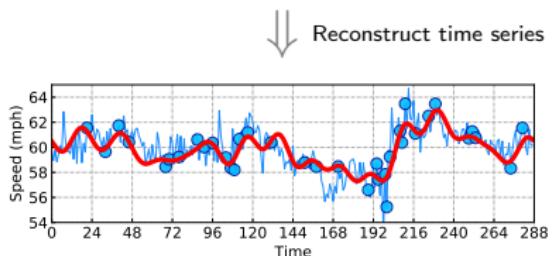
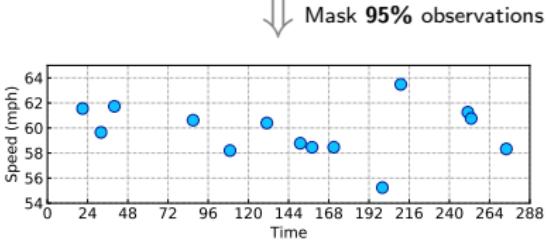
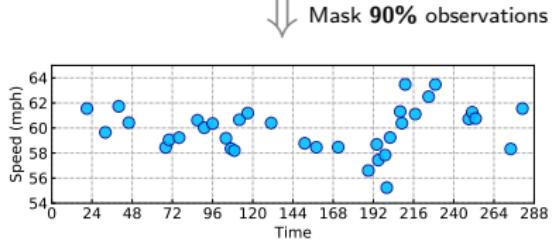
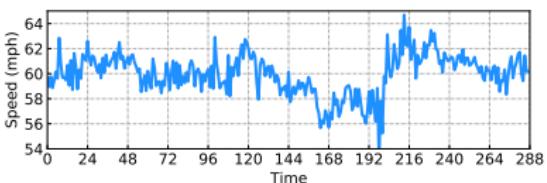
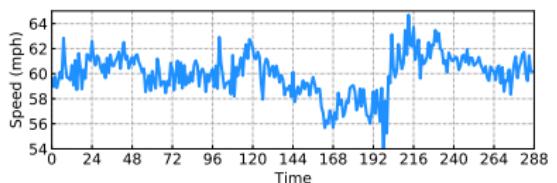
↓ Mask 90% observations



↓ Reconstruct time series



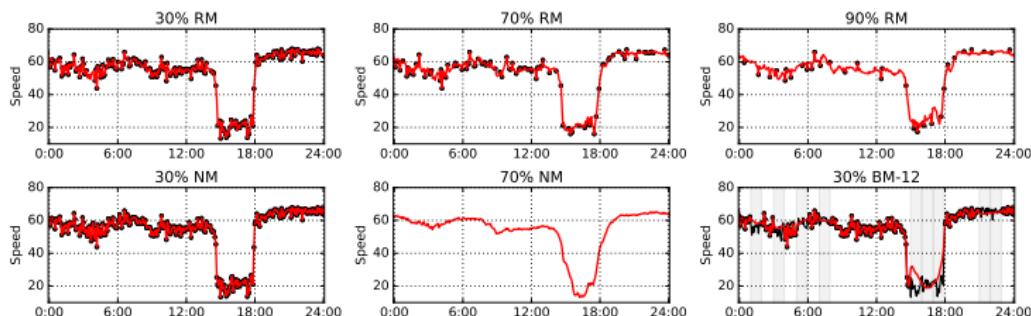
Univariate Traffic Time Series Imputation



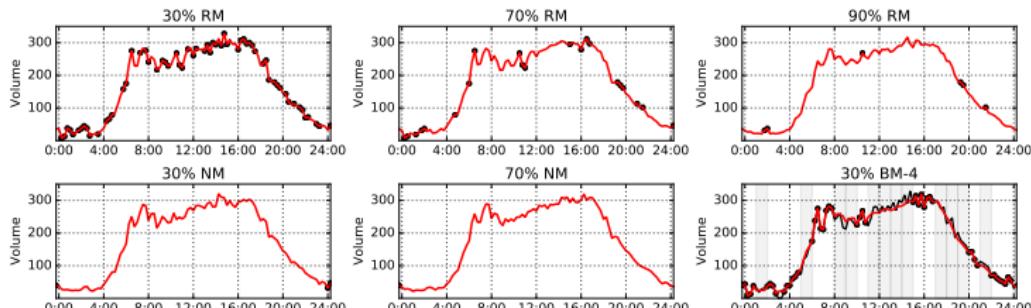
Spatiotemporal Traffic Data Imputation

LATC imputation

- Seattle freeway traffic speed data



- Portland highway traffic volume data



Background
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Literature Review
oooo

NoTMF
oooooo

LATC
ooooooo

LCR
oooooooo

HTF
ooooooooo

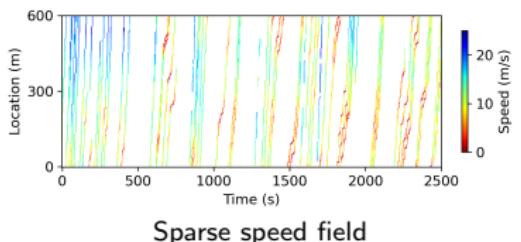
Experiments
oooo●oo

Conclusion
ooooo

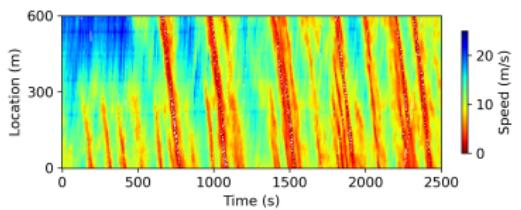
Large-Scale Traffic Data Imputation

LCR

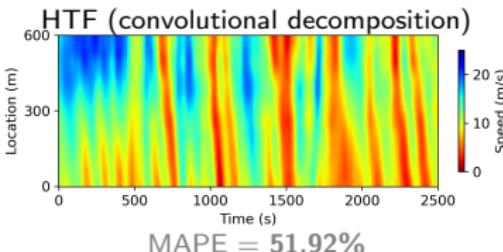
Extreme Missing Traffic Data Imputation



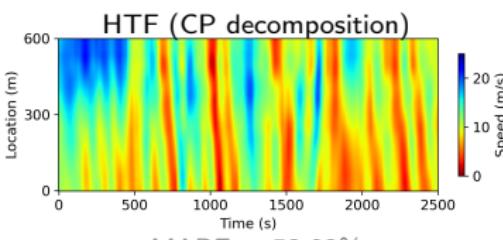
Sparse speed field



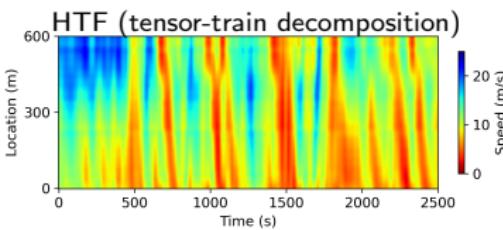
Ground truth speed field



MAPE = 51.92%



MAPE = 53.93%



MAPE = 56.48%

Sparse Urban Traffic State Forecasting

NoTMF

Background
oooooooo

Literature Review
oooo

NoTMF
oooooo

LATC
ooooooo

LCR
oooooooo

HTF
ooooooooo

Experiments
ooooooo

Conclusion
●oooo

Conclusion

- Data (large-scale, high-dimensional, city-wide, sparse)
- Modeling (meaningfulness and importance of temporal correlations)

Conclusion

Time-Varying Autoregression:

- (Highlight) Interpretable model with tensor factorization.
 - ✓ Parameter compression ✓ Pattern discovery

Laplacian Convolutional Representation:

- (Solution) Time series trend modeling in the low-rank framework?
 - Global time series trend modeling (low-rank model):

$$\begin{aligned} & \min_{\mathbf{x}} \|\mathcal{C}(\mathbf{x})\|_* \\ & \text{ s. t. } \|\mathcal{P}_\Omega(\mathbf{x} - \mathbf{y})\|_2 \leq \epsilon \end{aligned}$$

- Local time series trend modeling (temporal regularization):

$$\mathcal{R}_\tau(\mathbf{x}) = \frac{1}{2} \|\boldsymbol{\ell} * \mathbf{x}\|_2^2$$

- (Highlight) A unified framework with the **FFT** implementation.

Hankel Tensor Factorization:

- (Highlight) Memory-efficient **Hankel indexing & convolutional parameterization**.

Our studies:

- ② X. Chen, Z. Cheng, N. Saunier, L. Sun (2022). Laplacian convolutional representation for traffic time series imputation. arXiv preprint arXiv:2212.01529.
- ③ X. Chen, L. Sun (2022). Bayesian temporal factorization for multidimensional time series prediction. IEEE Transactions on Pattern Analysis and Machine Intelligence. 44 (9): 4659-4673.

GitHub repository:

- **transdim**: Machine learning for spatiotemporal traffic data imputation and forecasting. (1,000 stars & 270 forks on GitHub)
<https://github.com/xinychen/transdim>



Dr. HanQin Cai



Xiaoxu Chen



Dr. Zhanhong Cheng



Chengyuan Zhang



Dr. Xi-Le Zhao



Thanks for your attention!

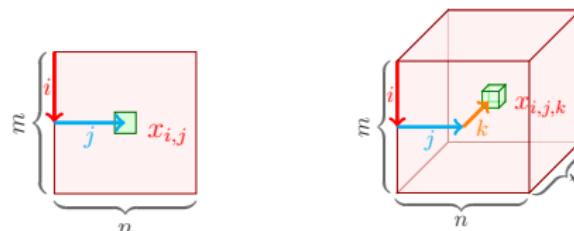
Any Questions?

About me:

- Homepage: <https://xinychen.github.io>
- GitHub: <https://github.com/xinychen>
- How to reach me: chenxy346@gmail.com

What Is Tensors?

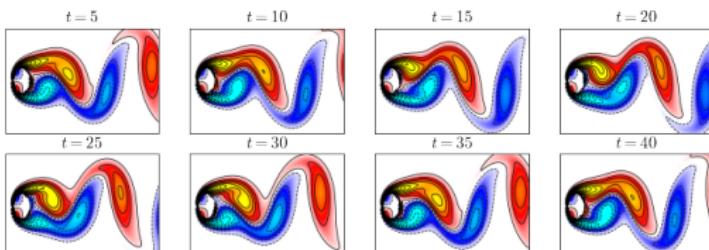
- What is tensor? $\mathbf{X} \in \mathbb{R}^{m \times n}$ vs. $\mathcal{X} \in \mathbb{R}^{m \times n \times t}$



- Tensors are everywhere!



Color image with
RGB channels



Dynamical system (fluid flow)

Appendix