

A generalized signature method for multivariate time series classification

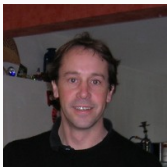
Second Symposium on Machine Learning and Dynamical Systems, Fields Institute, Toronto

Adeline Fermanian

September 25th 2020



Joint work with



Benoît Cadre

UNIVERSITY RENNES 2



Gérard Biau

SORBONNE UNIVERSITY



Terry Lyons

UNIVERSITY OF
OXFORD



Patrick Kidger

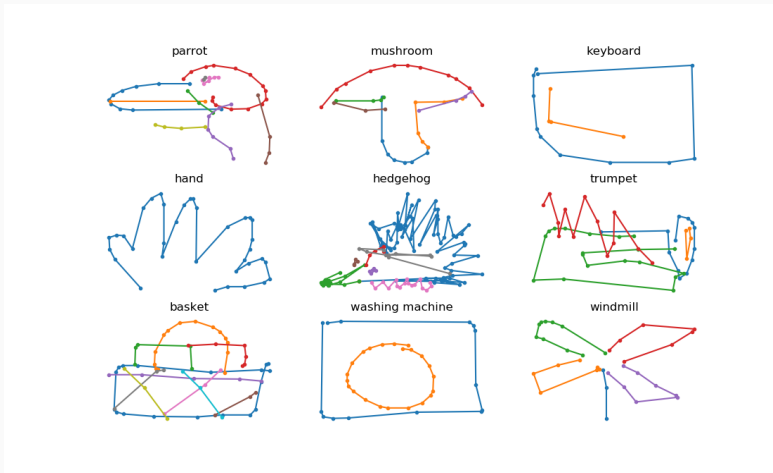
UNIVERSITY OF
OXFORD



James Morrill

UNIVERSITY OF
OXFORD

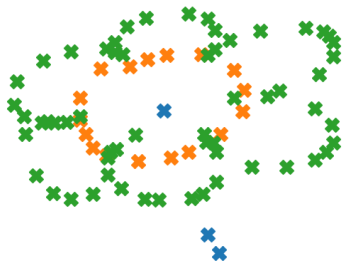
Time series classification



Characters recognition

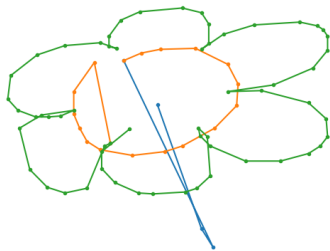
The predictor is a path $X : [a, b] \rightarrow \mathbb{R}^d$.

Data representation



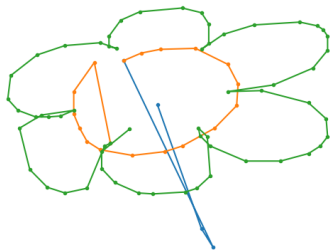
A sample from the class `flower`

Data representation

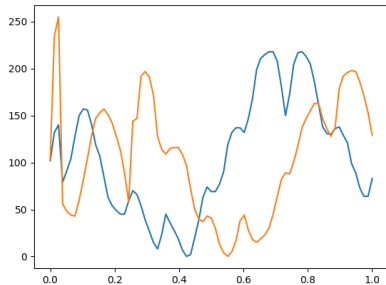


A sample from the class **flower**

Data representation

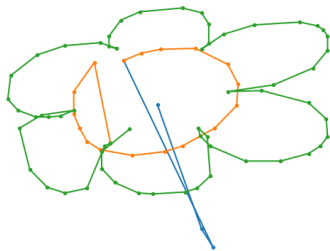


A sample from the class **flower**

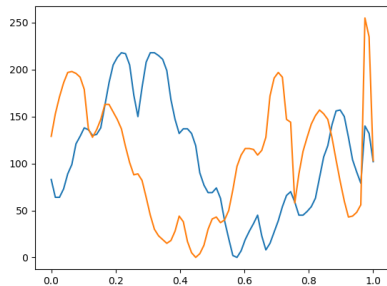


x and y **coordinates**

Data representation

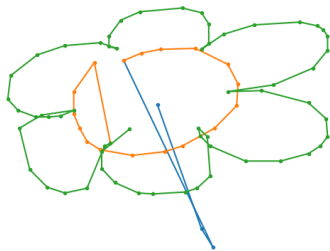


A sample from the class **flower**

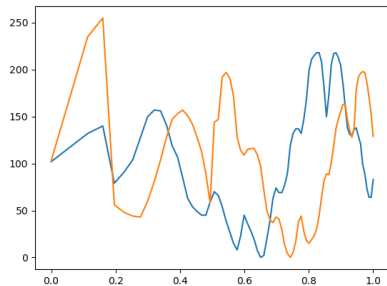


Time **reversed**

Data representation



A sample from the class **flower**



x and y at a **different** speed

The **signature** will overcome some of these problems.

The **signature** will overcome some of these problems.

- ▷ It is a **transformation** from a path to a sequence of coefficients.

The **signature** will overcome some of these problems.

- ▷ It is a **transformation** from a path to a sequence of coefficients.
- ▷ **Independent** of time parameterization.

The **signature** will overcome some of these problems.

- ▷ It is a **transformation** from a path to a sequence of coefficients.
- ▷ **Independent** of time parameterization.
- ▷ Encodes **geometric** properties of the path.

The **signature** will overcome some of these problems.

- ▷ It is a **transformation** from a path to a sequence of coefficients.
- ▷ **Independent** of time parameterization.
- ▷ Encodes **geometric** properties of the path.
- ▷ **No loss** of information.

Definition and basic properties

- A path $X : [0, 1] \rightarrow \mathbb{R}^d$. Notation: X_t .

- A path $X : [0, 1] \rightarrow \mathbb{R}^d$. Notation: X_t .
- Assumption: $\|X\|_{1\text{-var}} < \infty$.
- Path integral:

- A **path** $X : [0, 1] \rightarrow \mathbb{R}^d$. **Notation**: X_t .
- **Assumption**: $\|X\|_{1\text{-var}} < \infty$.
- **Path integral**:
 - X is differentiable, $Y : [0, 1] \rightarrow \mathbb{R}$ a **continuous** path.

$$\int_0^1 Y_t dX_t^i = \int_0^1 Y_t \dot{X}_t^i dt.$$

- A **path** $X : [0, 1] \rightarrow \mathbb{R}^d$. **Notation**: X_t .
- **Assumption**: $\|X\|_{1\text{-var}} < \infty$.
- **Path integral**:
 - X is differentiable, $Y : [0, 1] \rightarrow \mathbb{R}$ a **continuous** path.

$$\int_0^1 Y_t dX_t^i = \int_0^1 Y_t \dot{X}_t^i dt.$$

- Generalization to $\|X\|_{1\text{-var}} < \infty$ via the **Riemann-Stieltjes** integral.

Iterated integrals

- $X : [0, 1] \rightarrow \mathbb{R}^d$, $X = (X^1, \dots, X^d)$.

Iterated integrals

- $X : [0, 1] \rightarrow \mathbb{R}^d$, $X = (X^1, \dots, X^d)$.
- For $i \in \{1, \dots, d\}$,

$$S^i(X)_{[0,t]} = \int_{0 < s < t} dX_s^i = X_t^i - X_0^i$$

Iterated integrals

- $X : [0, 1] \rightarrow \mathbb{R}^d$, $X = (X^1, \dots, X^d)$.
- For $i \in \{1, \dots, d\}$,

$$S^i(X)_{[0,t]} = \int_{0 < s < t} dX_s^i = X_t^i - X_0^i \rightarrow \text{a path!}$$

Iterated integrals

- $X : [0, 1] \rightarrow \mathbb{R}^d$, $X = (X^1, \dots, X^d)$.
- For $i \in \{1, \dots, d\}$,

$$S^i(X)_{[0,t]} = \int_{0 < s < t} dX_s^i = X_t^i - X_0^i \rightarrow \text{a path!}$$

- For $(i, j) \in \{1, \dots, d\}^2$,

$$S^{i,j}(X)_{[0,t]} = \int_{0 < s < t} S^i(X)_{[0,s]} dX_s^j = \int_{0 < r < s < t} dX_r^i dX_s^j$$

Iterated integrals

- $X : [0, 1] \rightarrow \mathbb{R}^d$, $X = (X^1, \dots, X^d)$.
- For $i \in \{1, \dots, d\}$,

$$S^i(X)_{[0,t]} = \int_{0 < s < t} dX_s^i = X_t^i - X_0^i \rightarrow \text{a path!}$$

- For $(i, j) \in \{1, \dots, d\}^2$,

$$S^{i,j}(X)_{[0,t]} = \int_{0 < s < t} S^i(X)_{[0,s]} dX_s^j = \int_{0 < r < s < t} dX_r^i dX_s^j \rightarrow \text{a path!}$$

Iterated integrals

- $X : [0, 1] \rightarrow \mathbb{R}^d$, $X = (X^1, \dots, X^d)$.
- For $i \in \{1, \dots, d\}$,

$$S^i(X)_{[0,t]} = \int_{0 < s < t} dX_s^i = X_t^i - X_0^i \rightarrow \text{a path!}$$

- For $(i, j) \in \{1, \dots, d\}^2$,

$$S^{i,j}(X)_{[0,t]} = \int_{0 < s < t} S^i(X)_{[0,s]} dX_s^j = \int_{0 < r < s < t} dX_r^i dX_s^j \rightarrow \text{a path!}$$

- **Recursively**, for $(i_1, \dots, i_k) \in \{1, \dots, d\}^k$,

$$S^{(i_1, \dots, i_k)}(X)_{[0,t]} = \int_{0 < t_1 < t_2 < \dots < t_k < t} dX_{t_1}^{i_1} \dots dX_{t_k}^{i_k}.$$

Iterated integrals

- $X : [0, 1] \rightarrow \mathbb{R}^d$, $X = (X^1, \dots, X^d)$.
- For $i \in \{1, \dots, d\}$,

$$S^i(X)_{[0,t]} = \int_{0 < s < t} dX_s^i = X_t^i - X_0^i \rightarrow \text{a path!}$$

- For $(i, j) \in \{1, \dots, d\}^2$,

$$S^{i,j}(X)_{[0,t]} = \int_{0 < s < t} S^i(X)_{[0,s]} dX_s^j = \int_{0 < r < s < t} dX_r^i dX_s^j \rightarrow \text{a path!}$$

- **Recursively**, for $(i_1, \dots, i_k) \in \{1, \dots, d\}^k$,

$$S^{(i_1, \dots, i_k)}(X)_{[0,t]} = \int_{0 < t_1 < t_2 < \dots < t_k < t} dX_{t_1}^{i_1} \dots dX_{t_k}^{i_k}.$$

- $S^{(i_1, \dots, i_k)}(X)_{[0,1]}$ is the **k -fold iterated integral** of X along i_1, \dots, i_k .

Definition

The **signature** of X is the sequence of real numbers

$$S(X) = (1, S^1(X), \dots, S^d(X), S^{(1,1)}(X), S^{(1,2)}(X), \dots).$$

Signature

Definition

The **signature** of X is the sequence of real numbers

$$S(X) = (1, S^1(X), \dots, S^d(X), S^{(1,1)}(X), S^{(1,2)}(X), \dots).$$

- $d = 3 \rightarrow (1, 2, 3, 11, 12, 13, 21, 22, 23, 31, 32, 33, 111, 112, 113, \dots)$

Definition

The **signature** of X is the sequence of real numbers

$$S(X) = (1, S^1(X), \dots, S^d(X), S^{(1,1)}(X), S^{(1,2)}(X), \dots).$$

- $d = 3 \rightarrow (1, 2, 3, 11, 12, 13, 21, 22, 23, 31, 32, 33, 111, 112, 113, \dots)$
- **Tensor** notation:

$$X^k = \sum_{(i_1, \dots, i_k) \subset \{1, \dots, d\}^k} S^{(i_1, \dots, i_k)}(X) e_{i_1} \otimes \dots \otimes e_{i_k}.$$

Definition

The **signature** of X is the sequence of real numbers

$$S(X) = (1, S^1(X), \dots, S^d(X), S^{(1,1)}(X), S^{(1,2)}(X), \dots).$$

- $d = 3 \rightarrow (1, 2, 3, 11, 12, 13, 21, 22, 23, 31, 32, 33, 111, 112, 113, \dots)$
- **Tensor** notation:

$$X^k = \sum_{(i_1, \dots, i_k) \subset \{1, \dots, d\}^k} S^{(i_1, \dots, i_k)}(X) e_{i_1} \otimes \dots \otimes e_{i_k}.$$

- **Signature:**

$$S(X) = (1, X^1, X^2, \dots, X^k, \dots) \in T(\mathbb{R}^d),$$

Definition

The **signature** of X is the sequence of real numbers

$$S(X) = (1, S^1(X), \dots, S^d(X), S^{(1,1)}(X), S^{(1,2)}(X), \dots).$$

- $d = 3 \rightarrow (1, 2, 3, 11, 12, 13, 21, 22, 23, 31, 32, 33, 111, 112, 113, \dots)$
- **Tensor** notation:

$$X^k = \sum_{(i_1, \dots, i_k) \subset \{1, \dots, d\}^k} S^{(i_1, \dots, i_k)}(X) e_{i_1} \otimes \dots \otimes e_{i_k}.$$

- **Signature:**

$$S(X) = (1, X^1, X^2, \dots, X^k, \dots) \in T(\mathbb{R}^d),$$

where

$$T(\mathbb{R}^d) = 1 \oplus \mathbb{R}^d \oplus (\mathbb{R}^d)^{\otimes 2} \oplus \dots \oplus (\mathbb{R}^d)^{\otimes k} \oplus \dots$$

Example

For $X_t = (X_t^1, X_t^2)$,

$$X^1 = \left(\int_0^1 dX_t^1 \quad \int_0^1 dX_t^2 \right) = \left(X_1^1 - X_0^1 \quad X_1^2 - X_0^2 \right)$$

Example

For $X_t = (X_t^1, X_t^2)$,

$$X^1 = \left(\int_0^1 dX_t^1 \quad \int_0^1 dX_t^2 \right) = \left(X_1^1 - X_0^1 \quad X_1^2 - X_0^2 \right)$$


$$X^2 = \begin{pmatrix} \int_0^1 \int_0^t dX_s^1 dX_t^1 & \int_0^1 \int_0^t dX_s^1 dX_t^2 \\ \int_0^1 \int_0^t dX_s^2 dX_t^1 & \int_0^1 \int_0^t dX_s^2 dX_t^2 \end{pmatrix}$$


Example

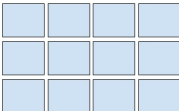
For $X_t = (X_t^1, X_t^2)$,

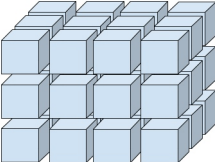
$$X^1 = \left(\int_0^1 dX_t^1 \quad \int_0^1 dX_t^2 \right) = \left(X_1^1 - X_0^1 \quad X_1^2 - X_0^2 \right)$$

$$X^2 = \begin{pmatrix} \int_0^1 \int_0^t dX_s^1 dX_t^1 & \int_0^1 \int_0^t dX_s^1 dX_t^2 \\ \int_0^1 \int_0^t dX_s^2 dX_t^1 & \int_0^1 \int_0^t dX_s^2 dX_t^2 \end{pmatrix}$$

Rank 0: 
(scalar)

Rank 1: 
(vector)

Rank 2: (matrix)


Rank 3: 

- **Truncated signature** at order m :

$$S^m(X) = (1, X^1, X^2, \dots, X^m).$$

Truncated signature

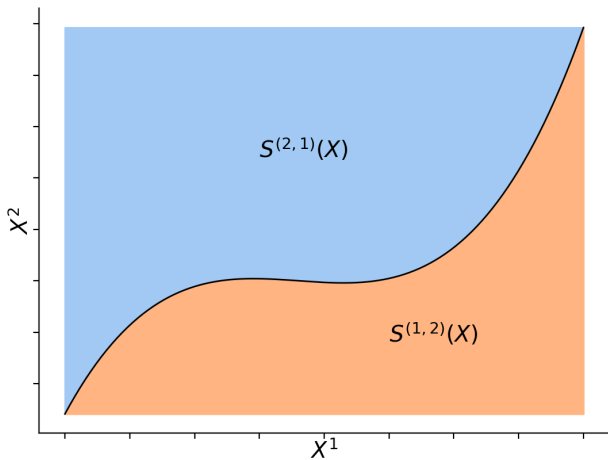
- **Truncated signature** at order m :

$$S^m(X) = (1, X^1, X^2, \dots, X^m).$$

- **Dimension:**

$$s_d(m) = \sum_{k=0}^m d^k = \frac{d^{m+1} - 1}{d - 1}.$$

Geometric interpretation



Important example

Linear path

- $X : [0, 1] \rightarrow \mathbb{R}^d$ a linear path.

Important example

Linear path

- $X : [0, 1] \rightarrow \mathbb{R}^d$ a linear path.
- $X_t = X_0 + (X_1 - X_0)t$.

Linear path

- $X : [0, 1] \rightarrow \mathbb{R}^d$ a linear path.
- $X_t = X_0 + (X_1 - X_0)t$.
- For any $I = (i_1, \dots, i_k)$,

$$S^I(X) = \frac{1}{k!} \prod_{j=1}^k (X_1 - X_0)^{i_j}.$$

Linear path

- $X : [0, 1] \rightarrow \mathbb{R}^d$ a linear path.
- $X_t = X_0 + (X_1 - X_0)t$.
- For any $I = (i_1, \dots, i_k)$,

$$S^I(X) = \frac{1}{k!} \prod_{j=1}^k (X_1 - X_0)^{i_j}.$$

- ▷ **Very useful**: in practice, we always deal with **piecewise linear** paths.
- ▷ Needed: **concatenation** operations.

Chen's identity

- $X : [a, b] \rightarrow \mathbb{R}^d$ and $Y : [b, c] \rightarrow \mathbb{R}^d$ paths.

Chen's identity

- $X : [a, b] \rightarrow \mathbb{R}^d$ and $Y : [b, c] \rightarrow \mathbb{R}^d$ paths.
- $X * Y : [a, c] \rightarrow \mathbb{R}^d$ the **concatenation**.

Chen's identity

- $X : [a, b] \rightarrow \mathbb{R}^d$ and $Y : [b, c] \rightarrow \mathbb{R}^d$ paths.
- $X * Y : [a, c] \rightarrow \mathbb{R}^d$ the **concatenation**.
- Then

$$S(X * Y) = S(X) \otimes S(Y).$$

Chen's identity

- $X : [a, b] \rightarrow \mathbb{R}^d$ and $Y : [b, c] \rightarrow \mathbb{R}^d$ paths.
- $X * Y : [a, c] \rightarrow \mathbb{R}^d$ the **concatenation**.
- Then

$$S(X * Y) = S(X) \otimes S(Y).$$

- ▷ We can compute the signature of **piecewise linear** paths!
- ▷ Data stream of p points and truncation at m : $O(pd^m)$ operations.
- ▷ **Fast** packages and libraries available in C++ and Python.

Uniqueness

If X has at least one **monotone coordinate**, then $S(X)$ determines X **uniquely** up to translations and reparametrizations.

Properties 2

Uniqueness

If X has at least one **monotone coordinate**, then $S(X)$ determines X **uniquely** up to translations and reparametrizations.

- ▷ The signature **characterizes** paths.
- ▷ **Trick**: add a dummy monotone component to X .
- ▷ Important concept of **augmentation**.

Signature approximation

- D compact subset of paths from $[0, 1]$ to \mathbb{R}^d that are not tree-like equivalent.

Signature approximation

- D compact subset of paths from $[0, 1]$ to \mathbb{R}^d that are not tree-like equivalent.
- $f : D \rightarrow \mathbb{R}$ continuous.

Signature approximation

- D compact subset of paths from $[0, 1]$ to \mathbb{R}^d that are not tree-like equivalent.
- $f : D \rightarrow \mathbb{R}$ continuous.
- Then, for every $\varepsilon > 0$, there exists $w \in T(\mathbb{R}^d)$ such that, for any $X \in D$,

$$|f(X) - \langle w, S(X) \rangle| \leq \varepsilon.$$

Signature approximation

- D compact subset of paths from $[0, 1]$ to \mathbb{R}^d that are not tree-like equivalent.
- $f : D \rightarrow \mathbb{R}$ continuous.
- Then, for every $\varepsilon > 0$, there exists $w \in T(\mathbb{R}^d)$ such that, for any $X \in D$,

$$|f(X) - \langle w, S(X) \rangle| \leq \varepsilon.$$

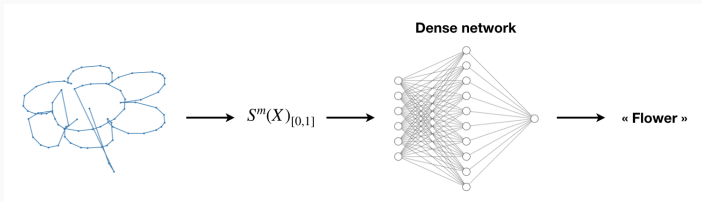
- ▷ Signature and linear model are happy together!
- ▷ This raises many interesting statistical issues.

Conclusion

- ▷ The signature is a **good descriptor** of a path: combine it with any machine learning “black box” algorithm.

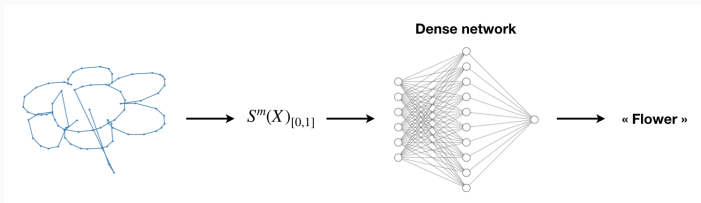
Conclusion

- ▷ The signature is a **good descriptor** of a path: combine it with any machine learning “black box” algorithm.



Conclusion

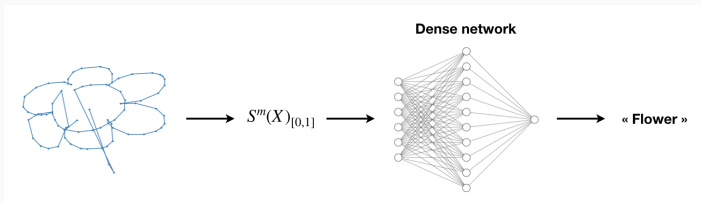
- ▷ The signature is a **good descriptor** of a path: combine it with any machine learning “black box” algorithm.



- ▷ **Flexible** tool and many choices: transformations to the path, domain of integration...

Conclusion

- ▷ The signature is a **good descriptor** of a path: combine it with any machine learning “black box” algorithm.



- ▷ **Flexible** tool and many choices: transformations to the path, domain of integration...
- ▷ Could we find a **canonical signature pipeline** that would be a domain-agnostic **starting point** for practitioners?

A generalized signature method

- **Goal:** systematic comparison of the different variations of the signature method.

- **Goal:** systematic comparison of the different variations of the signature method.
- Empirical study over **26 datasets** of time series classification.

- **Goal:** systematic comparison of the different variations of the signature method.
- Empirical study over **26 datasets** of time series classification.
- Define a **generalised signature method** as a framework to capture all these variations.

- **Goal:** systematic comparison of the different variations of the signature method.
- Empirical study over **26 datasets** of time series classification.
- Define a **generalised signature method** as a framework to capture all these variations.
- Give practitioners some simple, **domain-agnostic guidelines** for a first signature algorithm.

- **Input:** a sequence $x \in \mathcal{S}(\mathbb{R}^d)$, where

$$\mathcal{S}(\mathbb{R}^d) = \{(x_1, \dots, x_n) \mid x_i \in \mathbb{R}^d, n \in \mathbb{N}\}.$$

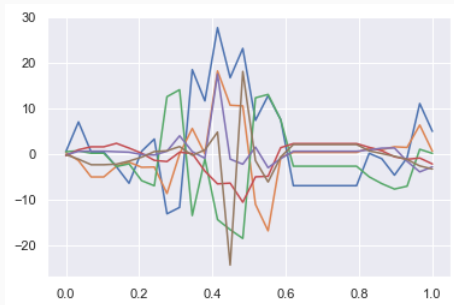
Framework

- **Input:** a sequence $x \in \mathcal{S}(\mathbb{R}^d)$, where

$$\mathcal{S}(\mathbb{R}^d) = \{(x_1, \dots, x_n) \mid x_i \in \mathbb{R}^d, n \in \mathbb{N}\}.$$



Racketsports dataset



A sample x with $d = 6$, $n = 30$

- **Input:** a sequence $x \in \mathcal{S}(\mathbb{R}^d)$, where

$$\mathcal{S}(\mathbb{R}^d) = \{(x_1, \dots, x_n) \mid x_i \in \mathbb{R}^d, n \in \mathbb{N}\}.$$

- **Output:** a label $y \in \{1, \dots, q\}$.

- **Input:** a sequence $x \in \mathcal{S}(\mathbb{R}^d)$, where

$$\mathcal{S}(\mathbb{R}^d) = \{(x_1, \dots, x_n) \mid x_i \in \mathbb{R}^d, n \in \mathbb{N}\}.$$

- **Output:** a label $y \in \{1, \dots, q\}$.
 - ▷ Racketsports dataset: $q = 4$
→ forehand squash, backhand squash, clear badminton, smash badminton.

▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

- ▷ Signature or logsignature transform: S^m .

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

- ▷ Signature or logsignature transform: S^m .
- ▷ **Rescaling** operation ρ_{post} or ρ_{pre} .

Framework

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

- ▷ Signature or logsignature transform: S^m .
- ▷ **Rescaling** operation ρ_{post} or ρ_{pre} .

Feature set

$$y_{i,j,k} = (\rho_{\text{post}} \circ S^m \circ \rho_{\text{pre}} \circ W^{i,j} \circ \phi^k)(x).$$

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

- ▷ Signature or logsignature transform: S^m .
- ▷ **Rescaling** operation ρ_{post} or ρ_{pre} .

Feature set

$$y_{i,j,k} = (\rho_{\text{post}} \circ S^m \circ \rho_{\text{pre}} \circ W^{i,j} \circ \phi^k)(x).$$

Different goals:

- ▷ **Sensitivity** to properties of the path.

Different goals:

- ▷ Sensitivity to properties of the path.
- ▷ Dimension reduction.

Different **goals**:

- ▷ **Sensitivity** to properties of the path.
- ▷ **Dimension reduction**.
- ▷ **Data-dependent** transformation → make the path **adapted** to signatures.

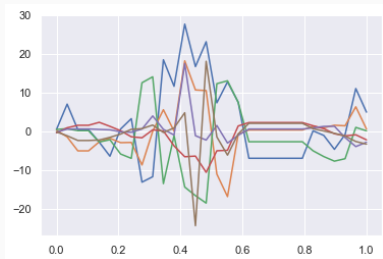
- Time augmentation

$$\phi(\mathbf{x}) = ((1, x_1), \dots, (n, x_n)) \in \mathcal{S}(\mathbb{R}^{d+1}).$$

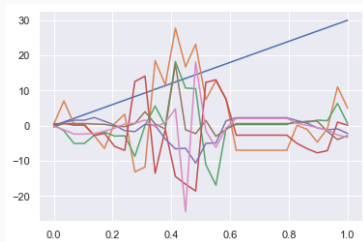
Augmentations

- Time augmentation

$$\phi(x) = ((1, x_1), \dots, (n, x_n)) \in \mathcal{S}(\mathbb{R}^{d+1}).$$



Sample $x \in \mathcal{S}(\mathbb{R}^6)$

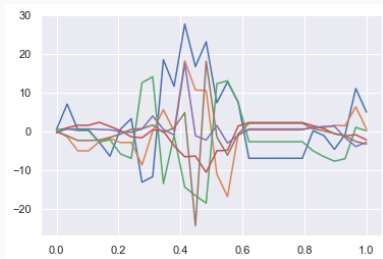


Augmented path $\phi(x) \in \mathcal{S}(\mathbb{R}^7)$

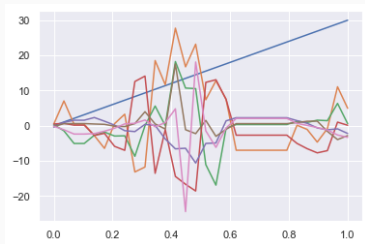
Augmentations

- Time augmentation

$$\phi(x) = ((1, x_1), \dots, (n, x_n)) \in \mathcal{S}(\mathbb{R}^{d+1}).$$



Sample $x \in \mathcal{S}(\mathbb{R}^6)$



Augmented path $\phi(x) \in \mathcal{S}(\mathbb{R}^7)$

- ▷ Sensitivity to parametrization and ensures signature uniqueness.

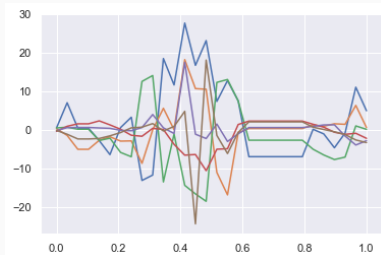
- Lead-lag augmentation

$$\phi(\mathbf{x}) = ((x_1, x_1), (x_2, x_1), (x_2, x_2), \dots, (x_n, x_n)) \in \mathcal{S}(\mathbb{R}^{2d}).$$

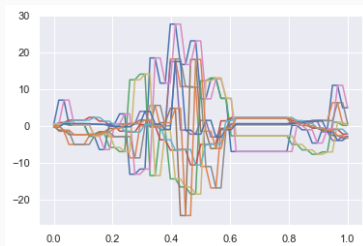
Augmentations

- Lead-lag augmentation

$$\phi(x) = ((x_1, x_1), (x_2, x_1), (x_2, x_2), \dots, (x_n, x_n)) \in \mathcal{S}(\mathbb{R}^{2d}).$$



Sample $x \in \mathcal{S}(\mathbb{R}^6)$

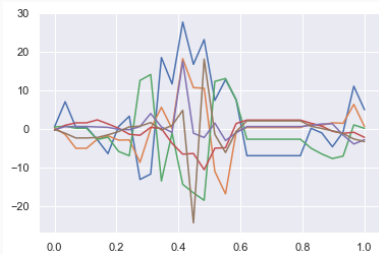


Augmented path $\phi(x) \in \mathcal{S}(\mathbb{R}^{12})$

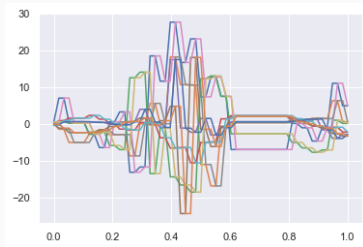
Augmentations

- Lead-lag augmentation

$$\phi(x) = ((x_1, x_1), (x_2, x_1), (x_2, x_2), \dots, (x_n, x_n)) \in \mathcal{S}(\mathbb{R}^{2d}).$$



Sample $x \in \mathcal{S}(\mathbb{R}^6)$



Augmented path $\phi(x) \in \mathcal{S}(\mathbb{R}^{12})$

- ▷ Captures the **quadratic variation** of a process.

- Basepoint augmentation

$$\phi(x) = (0, x_1, \dots, x_n) \in \mathcal{S}(\mathbb{R}^d).$$

- Basepoint augmentation

$$\phi(x) = (0, x_1, \dots, x_n) \in \mathcal{S}(\mathbb{R}^d).$$

- Invisibility-reset augmentation

$$\phi(x) = ((1, x_1), \dots, (1, x_{n-1}), (1, x_n), (0, x_n), (0, 0)) \in \mathcal{S}(\mathbb{R}^{d+1}).$$

- Basepoint augmentation

$$\phi(x) = (0, x_1, \dots, x_n) \in \mathcal{S}(\mathbb{R}^d).$$

- Invisibility-reset augmentation

$$\phi(x) = ((1, x_1), \dots, (1, x_{n-1}), (1, x_n), (0, x_n), (0, 0)) \in \mathcal{S}(\mathbb{R}^{d+1}).$$

- ▷ Sensitivity to **translations**.

Framework

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

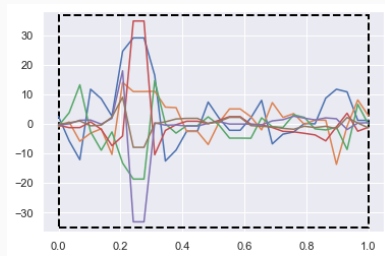
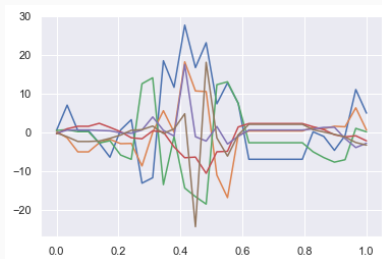
- ▷ Signature or logsignature transform: S^m .
- ▷ **Rescaling** operation ρ_{post} or ρ_{pre} .

Feature set

$$y_{i,j,k} = (\rho_{\text{post}} \circ S^m \circ \rho_{\text{pre}} \circ W^{i,j} \circ \phi^k)(x).$$

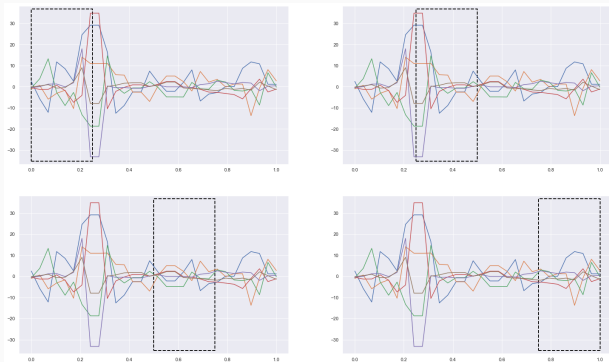
- Global window

$$W(x) = (x) \in \mathcal{S}(\mathbb{R}^e),$$



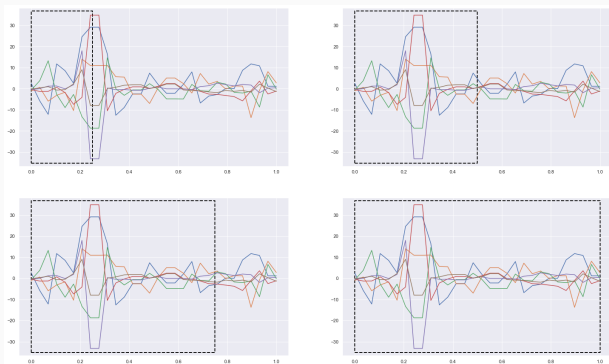
- Sliding window

$$W(x) = (x_{1,l}, x_{l+1, l+l}, x_{2l+1, 2l+l}, \dots) \in \mathcal{S}(\mathcal{S}(\mathbb{R}^e)),$$



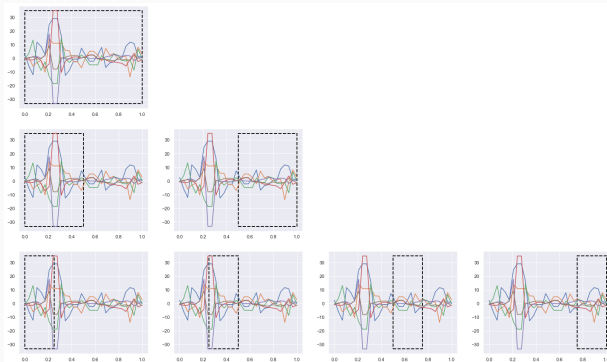
- Expanding window

$$W(x) = (x_{1,l}, x_{1,l+l}, x_{1,2l+l}, \dots) \in \mathcal{S}(\mathcal{S}(\mathbb{R}^e)).$$



- Dyadic window

$$W(x) = (W^1(x), \dots, W^q(x)) \in \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$



Framework

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

- ▷ Signature or logsignature transform: S^m .
- ▷ **Rescaling** operation ρ_{post} or ρ_{pre} .

Feature set

$$y_{i,j,k} = (\rho_{\text{post}} \circ S^m \circ \rho_{\text{pre}} \circ W^{i,j} \circ \phi^k)(x).$$

- Signature transform

$$S^m(x) = (1, X^1, X^2, \dots, X^m).$$

- Signature transform

$$S^m(x) = (1, X^1, X^2, \dots, X^m).$$

- Logsignature transform $\log(S^m(x))$, where for any $a \in T((\mathbb{R}^d))$,

$$\log(a) = \sum_{k \geq 0} \frac{(-1)^k}{k} (1 - a)^{\otimes k}.$$

- Signature transform

$$S^m(x) = (1, X^1, X^2, \dots, X^m).$$

- Logsignature transform $\log(S^m(x))$, where for any $a \in T((\mathbb{R}^d))$,

$$\log(a) = \sum_{k \geq 0} \frac{(-1)^k}{k} (1 - a)^{\otimes k}.$$

- ▷ Same information and logsignature less dimensional but no linear approximation property.

Signature versus logsignature

Table 1: Typical dimensions of $S^m(x)$ and $\log(S^m(x))$.

	$d = 2$	$d = 3$	$d = 6$
$m = 1$	2 / 2	3 / 3	6 / 6
$m = 2$	6 / 3	12 / 6	42 / 21
$m = 5$	62 / 14	363 / 80	9330 / 1960
$m = 7$	254 / 41	3279 / 508	335922 / 49685

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

- ▷ Signature or logsignature transform: S^m .
- ▷ **Rescaling** operation ρ_{post} or ρ_{pre} .

Feature set

$$y_{i,j,k} = (\rho_{\text{post}} \circ S^m \circ \rho_{\text{pre}} \circ W^{i,j} \circ \phi^k)(x).$$

Framework

- ▷ For some $e, p \in \mathbb{N}$, an **augmentation** is a map

$$\phi = (\phi^1, \dots, \phi^p): \mathcal{S}(\mathbb{R}^d) \rightarrow \mathcal{S}(\mathbb{R}^e)^p.$$

- ▷ For some $q \in \mathbb{N}$, a **window** is a map

$$W = (W^1, \dots, W^q): \mathcal{S}(\mathbb{R}^e) \rightarrow \mathcal{S}(\mathcal{S}(\mathbb{R}^e))^q.$$

- ▷ Signature or logsignature transform: S^m .
- ▷ **Rescaling** operation ρ_{post} or ρ_{pre} .

Feature set

$$y_{i,j,k} = (\rho_{\text{post}} \circ S^m \circ \rho_{\text{pre}} \circ W^{i,j} \circ \phi^k)(x).$$

- **26 datasets:** Human Activities and Postural Transitions, Speech Commands and 24 datasets from the UEA archive.

- **26 datasets:** Human Activities and Postural Transitions, Speech Commands and 24 datasets from the UEA archive.
- Definition of a **baseline:**

- **26 datasets**: Human Activities and Postural Transitions, Speech Commands and 24 datasets from the UEA archive.
- Definition of a **baseline**: time augmentation + global window + signature of depth 3 + pre-signature scaling

- **26 datasets**: Human Activities and Postural Transitions, Speech Commands and 24 datasets from the UEA archive.
- Definition of a **baseline**: time augmentation + global window + signature of depth 3 + pre-signature scaling

$$(S^3 \circ \rho_{\text{pre}} \circ \phi)(x).$$

- **26 datasets**: Human Activities and Postural Transitions, Speech Commands and 24 datasets from the UEA archive.
- Definition of a **baseline**: time augmentation + global window + signature of depth 3 + pre-signature scaling

$$(S^3 \circ \rho_{\text{pre}} \circ \phi)(x).$$

- Vary each group of options with regards to this baseline.

- **26 datasets**: Human Activities and Postural Transitions, Speech Commands and 24 datasets from the UEA archive.
- Definition of a **baseline**: time augmentation + global window + signature of depth 3 + pre-signature scaling

$$(S^3 \circ \rho_{\text{pre}} \circ \phi)(x).$$

- Vary each group of options with regards to this baseline.
- **4 classifiers**: logistic regression, random forest, GRU, CNN.

- **26 datasets**: Human Activities and Postural Transitions, Speech Commands and 24 datasets from the UEA archive.
- Definition of a **baseline**: time augmentation + global window + signature of depth 3 + pre-signature scaling

$$(S^3 \circ \rho_{\text{pre}} \circ \phi)(x).$$

- Vary each group of options with regards to this baseline.
- **4 classifiers**: logistic regression, random forest, GRU, CNN.

→ 9984 combinations.

- Evaluation of one combination: compute the **best accuracy** across the 4 classifiers.

- Evaluation of one combination: compute the **best accuracy** across the 4 classifiers.

Dataset	Window			
	Global	Sliding	Expanding	Dyadic
ArticulatoryWordRecognition	96.3%	89.3%	99.0%	99.0%
AtrialFibrillation	46.7%	46.7%	46.7%	60.0%
BasicMotions	100.0%	100.0%	100.0%	100.0%
CharacterTrajectories	93.2%	94.6%	96.9%	97.1%
Cricket	97.2%	93.1%	97.2%	95.8%
.
.
.

- Evaluation of one combination: compute the **best accuracy** across the 4 classifiers.
- Compute the average rank over all datasets.

Dataset	Window			
	Global	Sliding	Expanding	Dyadic
ArticularyWordRecognition	96.3%	89.3%	99.0%	99.0%
AtrialFibrillation	46.7%	46.7%	46.7%	60.0%
BasicMotions	100.0%	100.0%	100.0%	100.0%
CharacterTrajectories	93.2%	94.6%	96.9%	97.1%
Cricket	97.2%	93.1%	97.2%	95.8%
⋮	⋮	⋮	⋮	⋮
⋮	⋮	⋮	⋮	⋮

- Evaluation of one combination: compute the **best accuracy** across the 4 classifiers.
- Compute the average rank over all datasets.

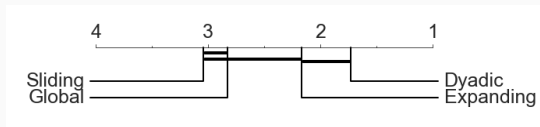
Dataset	Window			
	Global	Sliding	Expanding	Dyadic
ArticularyWordRecognition	3	4	1.5	1.5
AtrialFibrillation	3	3	3	1
BasicMotions	2	2	2	2
CharacterTrajectories	4	3	2	1
Cricket	1.5	4	1.5	3
.
.

- Evaluation of one combination: compute the **best accuracy** across the 4 classifiers.
- Compute the average rank over all datasets.

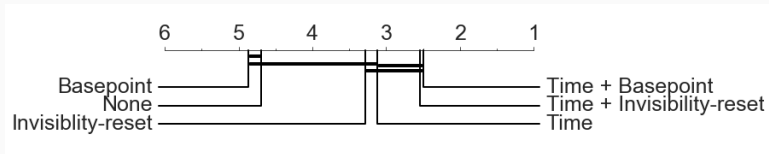
Dataset	Window			
	Global	Sliding	Expanding	Dyadic
ArticularyWordRecognition	3	4	1.5	1.5
AtrialFibrillation	3	3	3	1
BasicMotions	2	2	2	2
CharacterTrajectories	4	3	2	1
Cricket	1.5	4	1.5	3
.
.
.
Average ranks	2.83	3.04	2.17	1.73

- Evaluation of one combination: compute the **best accuracy** across the 4 classifiers.
- Compute the average rank over all datasets.
- Use a **critical differences plot**, a global Friedman test, and **pairwise** Wilcoxon signed-rank tests at 5% with Holm's alpha correction.

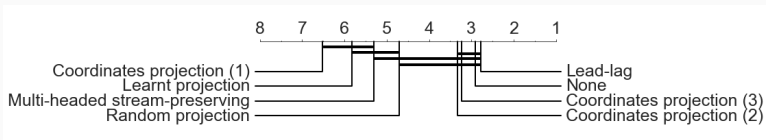
▷ Windows:



▷ Invariance-removing augmentations:



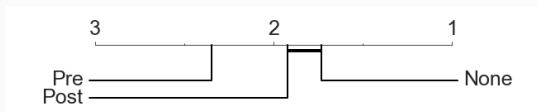
▷ Other augmentations:



- ▷ Signature versus logsignature transform:

	Signature	Logsignature
Average ranks	1.25	1.75
p-value		0.01

▷ Rescalings:



- ▷ Unless the problem is known to be translation or reparameterisation invariant, then use the **time and basepoint augmentations**.

Canonical signature pipeline

- ▷ Unless the problem is known to be translation or reparameterisation invariant, then use the **time and basepoint augmentations**.
- ▷ The **lead-lag** augmentation should be considered, but we do not recommend it in general, due to its **computational cost**.

Canonical signature pipeline

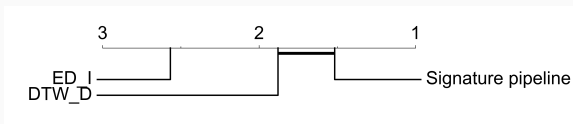
- ▷ Unless the problem is known to be translation or reparameterisation invariant, then use the **time and basepoint augmentations**.
- ▷ The **lead-lag** augmentation should be considered, but we do not recommend it in general, due to its **computational cost**.
- ▷ Use **hierarchical dyadic windows**, and the signature transform; both have a depth hyperparameter that must be optimised.

Canonical signature pipeline

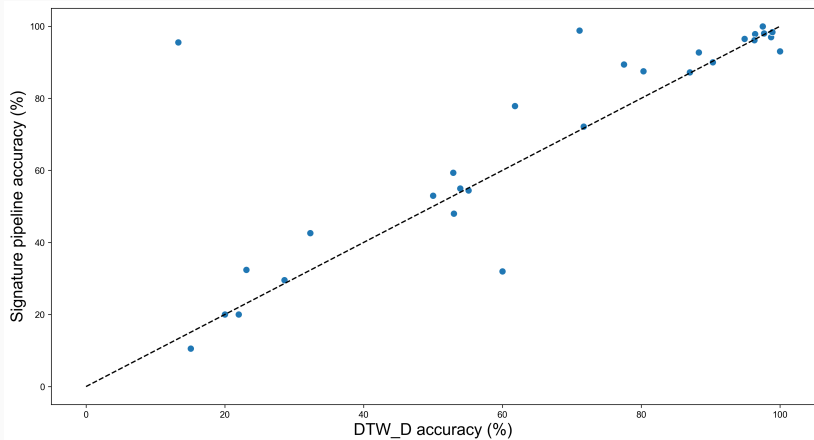
→ Implement this pipeline on the 30 datasets from the UEA archive and compare it to **benchmark** classifiers.

Canonical signature pipeline

→ Implement this pipeline on the 30 datasets from the UEA archive and compare it to **benchmark** classifiers.



Canonical signature pipeline



- Signatures are a **flexible** tool.

Conclusion

- Signatures are a **flexible** tool.
- We are able to find a **canonical signature method** that represents a **domain-agnostic** starting point.

Conclusion

- Signatures are a **flexible** tool.
- We are able to find a **canonical signature method** that represents a **domain-agnostic** starting point.
- The **combination** “signature + generic algorithm” \approx **state-of-the-art**.

Conclusion

- Signatures are a **flexible** tool.
- We are able to find a **canonical signature method** that represents a **domain-agnostic** starting point.
- The **combination** “signature + generic algorithm” \approx **state-of-the-art**.
- **Few** computing resources and **no** domain-specific knowledge.

Conclusion

- Signatures are a **flexible** tool.
- We are able to find a **canonical signature method** that represents a **domain-agnostic** starting point.
- The **combination** “signature + generic algorithm” \approx **state-of-the-art**.
- **Few** computing resources and **no** domain-specific knowledge.
- A lot of **open** questions and potential applications.

Thank you!