

Dynamic Grouped Mixture Models for Intermittent Multivariate Sensor Data

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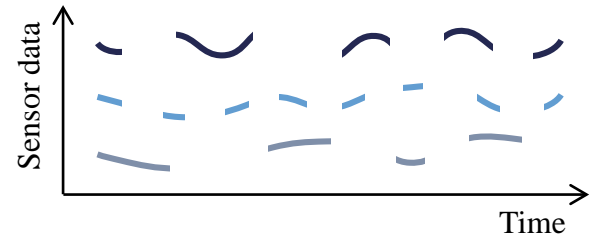
Background

Anomaly detection on “dirty” sensor data

- Major issue: anomaly detection for engineering systems
 - plants, vehicles, artificial satellites, ...



- Engineering systems generate “dirty” sensor data ☹
 - **irregular sampling rates**
 - **many missing values**
 - large noises etc.

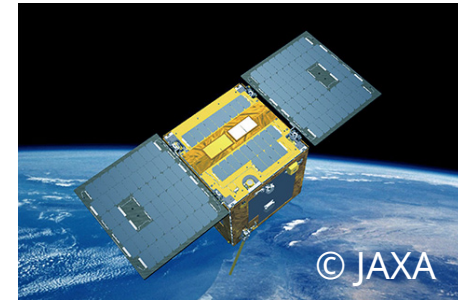


- How to **tackle “dirtiness”** of sensor data?
 - preprocessing will do a lot, but depends on data nature
 - models as simple as possible are desirable

Motivative Example

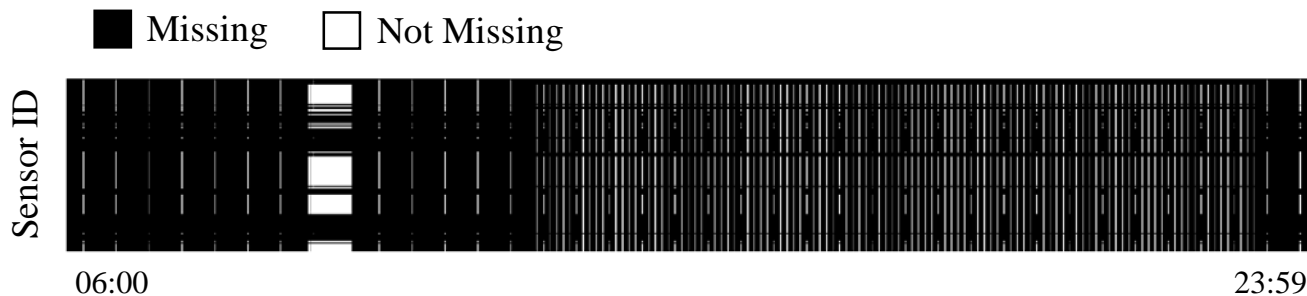
Telemetry sensor data of artificial satellite

- Data from **artificial satellite**
 - hundreds of sensors: voltmeters, thermometers, gyros, ...
 - hundreds of status indicators: on/off, operating modes, ...



Small Demonstration Satellite 4

- Those data are **uneven and sparse** due to limited amount of memory and transmission capability of satellites ☹



Example of measurement grids of satellite's sensor data

Purpose

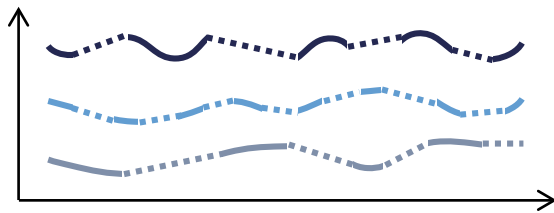
Modeling intermittent multivariate time-series

Modeling **Intermittent Multivariate Time-series** that are:

1. unevenly spaced ... sampling rate varies over time
2. temporally sparse ... many measurements are missing

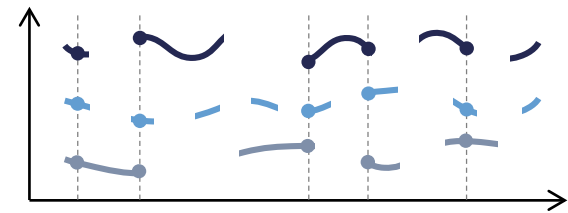
- Intuitive treatment in practice

Interpolation / Resampling



- 😊 OK with certain frequency
- 😞 vulnerable to noises

Forcing i.i.d. assumption

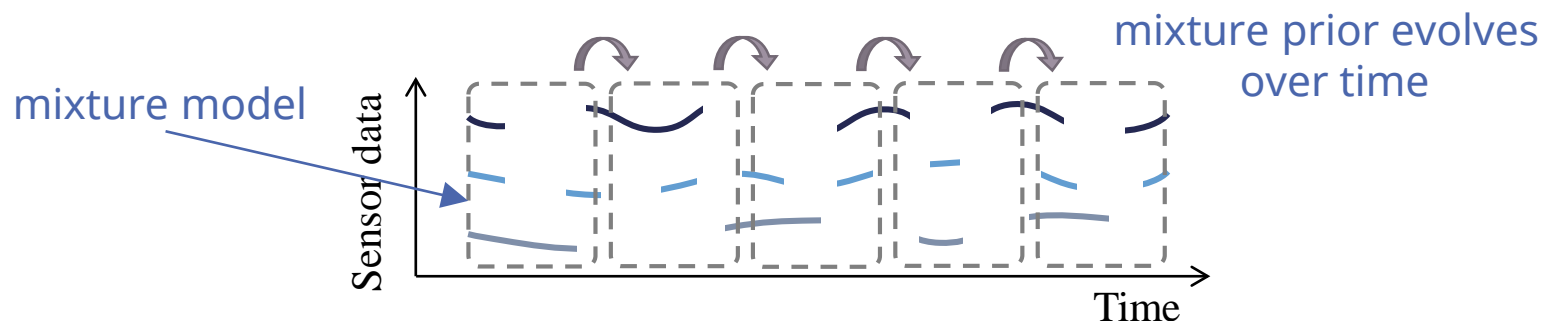


- 😊 interested in sensors' corr.
- 😞 lose temporal information

Approach

To “roughly” model temporal dependency

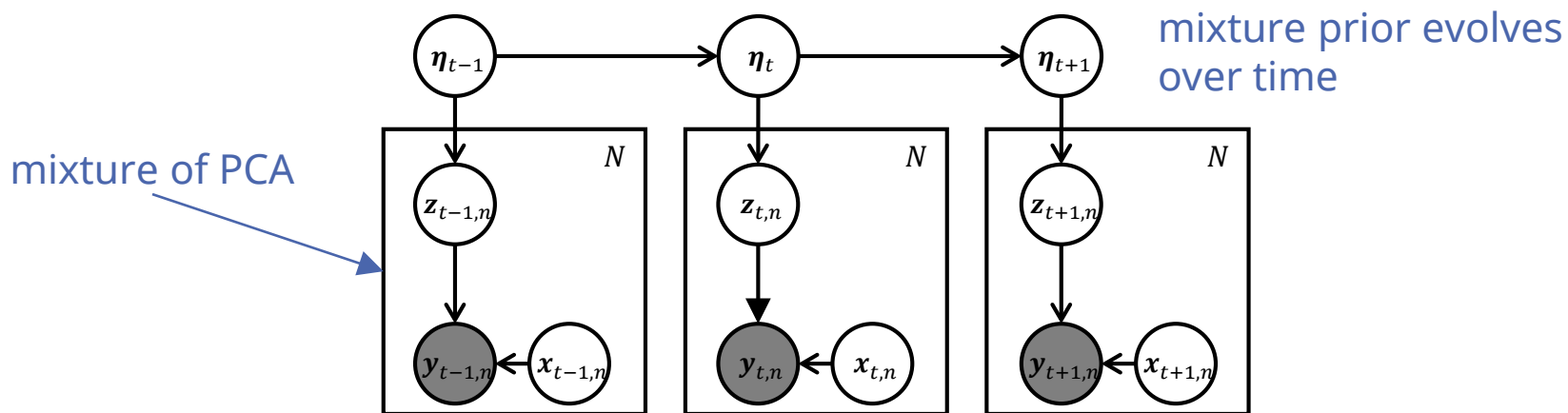
- Assumption: “dirty” time-series maintain **coarse temporal information**, even if the finest details are lost
- Want to salvage coarse sequentiality, by a model considering **groups of timestamps** instead of every single timestamps
 - put **mixture model** for each group of timestamps
 - make **prior on mixture assignments** to evolve over time



Generative Model

Dynamic Grouped Mixtures of PCAs

- **Partition time-series into groups** of timestamps.
- With regard to the t -th group of timestamps,
 1. Sample prior on mixture assignments: $\boldsymbol{\eta}_t | \boldsymbol{\eta}_{t-1} \sim \mathcal{N}(\boldsymbol{\eta}_{t-1}, \Lambda)$
 2. For $n = 1, \dots, N_t$,
 - a. Sample mix. component assignment: $\mathbf{z}_{t,n} | \boldsymbol{\eta}_t \sim \text{Cat}(\text{softmax}(\boldsymbol{\eta}_t))$
 - b. Sample latent factor: $\mathbf{x}_{t,n,k} \sim \mathcal{N}(\mathbf{0}, \mathbf{I})$ where $k \equiv z_{t,n}$
 - c. Sample observation: $\mathbf{y}_{t,n} | \mathbf{z}_{t,n}, \mathbf{x}_{t,n,k} \sim \mathcal{N}(\mathbf{L}_k \mathbf{x}_{t,n,k} + \mathbf{b}_k, \Psi_k)$



Inference and Learning

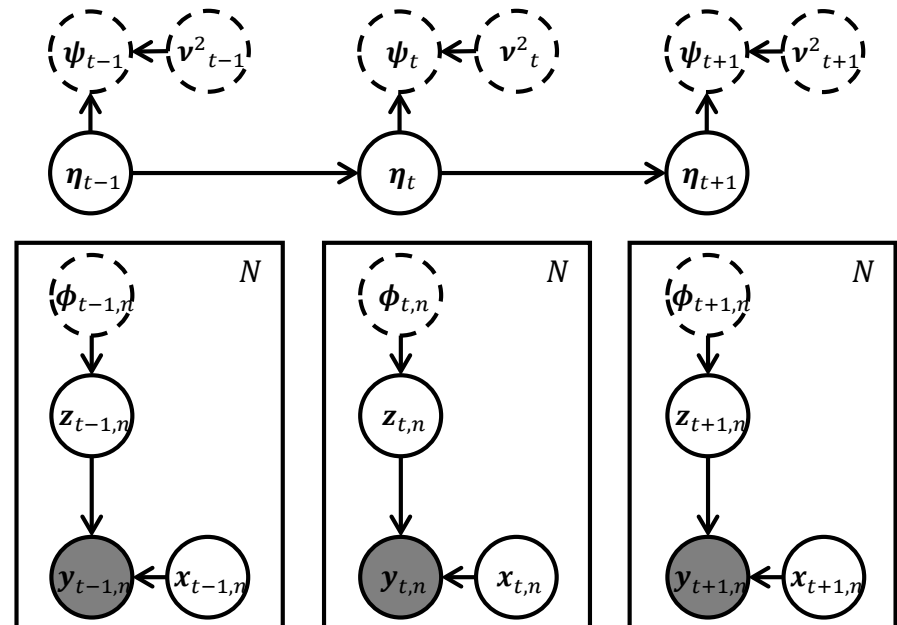
EM algorithm with variational Bayes

E-step VB iteration

- update ψ, v^2, ϕ
- Kalman filter for η
- inference of z, x

M-step optimize prms.

- Very similar to DTMs [Blei&Lafferty ICML'06]



Experiment 1

Time-series denoising

Task

- to denoise 8-dimensional time-series generated by a linear dynamical system (LDS),
→ i.e. to estimate $A\mathbf{x}_{1:N}$ given $\mathbf{y}_{1:N}$

$$\mathbf{y}_n = A\mathbf{x}_n + \mathbf{v}_n, \mathbf{v}_n \sim \mathcal{N}(\mathbf{0}, 0.1^2\mathbf{I})$$

$$\mathbf{x}_n = B\mathbf{x}_{n-1} + \mathbf{w}_n, \mathbf{w}_n \sim \mathcal{N}(\mathbf{0}, 0.1^2\mathbf{I})$$



- to simulate intermittency, time-series are **subsampled** by 0–80%

Result

- **original system, LDS**, fails at high subsamp. rates ☹️
- **our model** succeeds at high subsamp. rates 😊

RMS errors after denoising

		HMM	LDS	MPPCA	DGMPCA
Subsamp. Rate	0%	.280	.129	.177	.124
	20%	.304	.130	.169	.126
	40%	.315	.139	.170	.125
	60%	.319	.146	.198	.124
	80%	.345	.213	.192	.125

Experiment 2

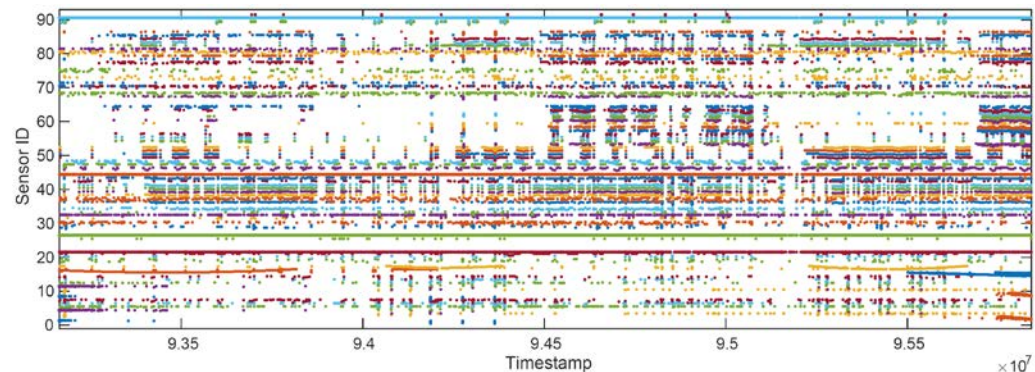
Visualization of satellite's sensor data

Task

- to visualize **everyday behavior of artificial satellite**, given its sensor data
- 92-dimensional data for 6 months
- measurements are missing irregularly from 3 to 12 hours
- visualization procedure:
 - divide data by days, and learn model with $\#mix.=10$
 - reduce dimensionality of mixture priors into 2, and plot it

Example of original sensor data of artificial satellite for a month

(plots are stacked for different sensors)

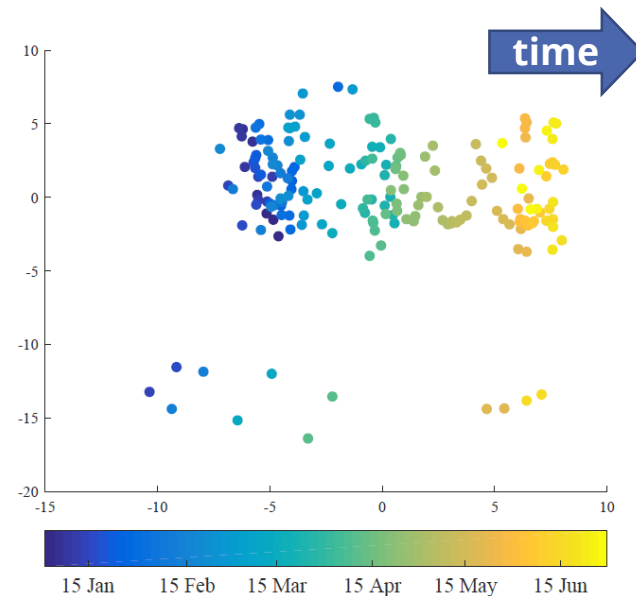
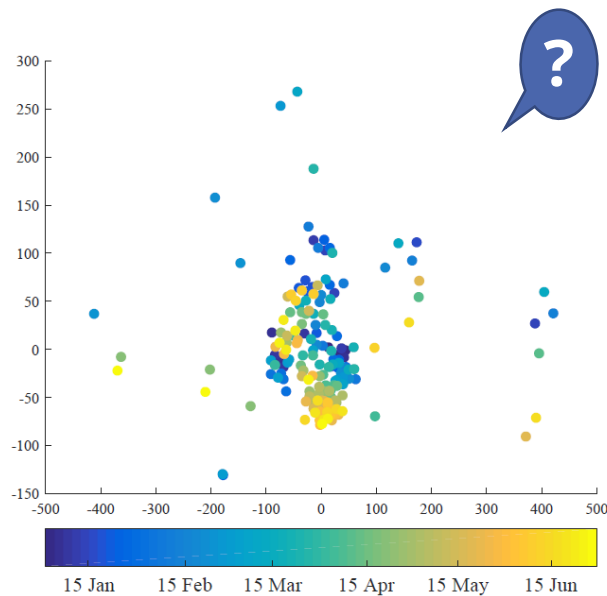


Experiment 2

Visualization of satellite's sensor data (cont.)

Result

- days are along **chronological order horizontally** with proposed method (right), while messed up with simple mixture model (left)

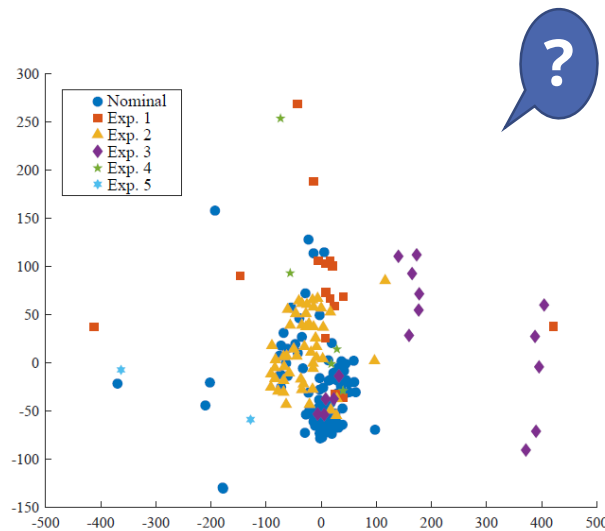


Experiment 2

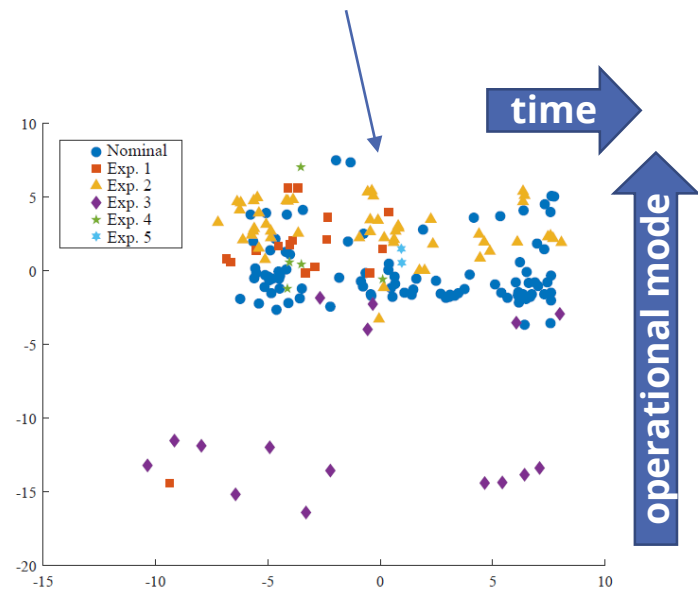
Visualization of satellite's sensor data (cont.)

Result

- we found that vertical axis can be utilized to understand **6 types of operational modes** on our satellite
 - ✓ mode "Exp. 1" (oranges) stopped at mid of April



Plots of each day with MPPCA



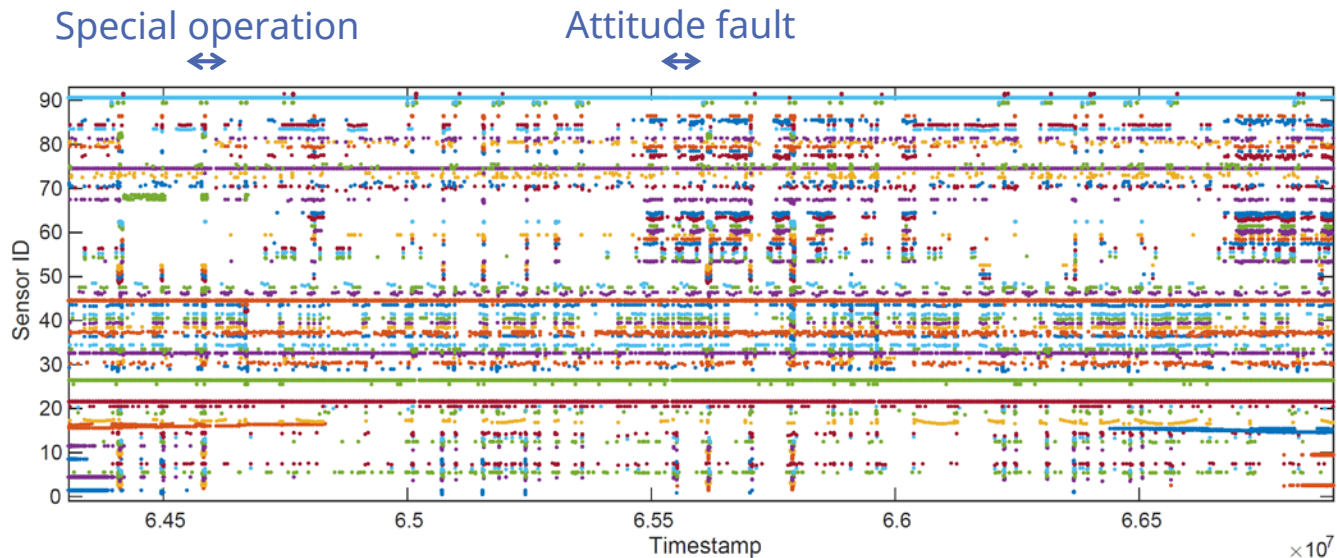
Plots of each day with **DGMPCA**

Experiment 3

Anomaly detection on sensor data

Task

- to detect anomalous behavior of an artificial satellite
- 1 month for training, another 1 month for validation
 - ✓ validation set contain no anomalous behavior ☹️



original test data (for 1 month) with anomalies

Experiment 3

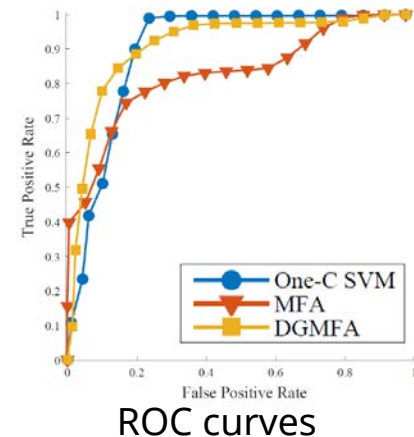
Anomaly detection on sensor data (cont.)

Result

- comparing 3 models including simple baselines A) and B)
 - A) OCSVM hyperprms tuned wrt. test performance (cheating!)
 - B) MPPCA hyperprms tuned wrt. validation likelihood
 - C) DGMPCA hyperprms tuned wrt. validation likelihood
- our method C) is better than i.i.d.-assumed model B), and better than cheating OCSVM A)

Area under ROC curves

A) One-class SVM	0.8998
B) MPPCA	0.8307
C) DGMPCA	0.9105



Summary

A “rough” time-series model for “dirty” data

- Sensor data are often dirty;
intermittent
- We proposed model:
dynamic grouped mixtures
- Considering **sequentiality of batches of measurements**
 - instead of every mes.
- Future possibilities
 - automatic grouping
 - connecting to dynamic topic models for text analyses

