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3 **Abstract**

Kernel methods are known to be effective to analyse complex objects by implicitly embedding them into some feature space. To interpret and analyse the obtained results, it is often required to restore in the input space the results obtained in the feature space, by using pre-image estimation methods. This work proposes a new closed-form pre-image estimation method for time series kernel analytics that consists of two steps. In the first step, a time warp function, driven by distance constraints in the feature space, is defined to embed time series in a metric space where analytics can be performed conveniently. In the second step, the time series pre-image estimation is cast as learning a linear (or a nonlinear) transformation that ensures a local isometry between the time series embedding space and the feature space. The proposed method is compared to the state of the art through three major tasks that require pre-image estimation: 1) time series averaging, 2) time series reconstruction and denoising and 3) time series representation learning. The extensive experiments conducted on 33 publicly-available datasets show the benefits of the pre-image estimation for time series kernel analytics.

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4 **1. Introduction**

5 Kernel methods [24] are well known to be effective in dealing with nonlin-  
6 ear machine learning problems in general, and are often required for machine  
7 learning tasks on complex data as sequences, time series or graphs. The main  
8 idea behind kernel machines is to map the data from the input space to a  
9 higher dimension feature space (i.e., kernel space) via a nonlinear map, where  
10 the mapped data can be then analysed by linear models. While the mapping  
11 from input space to the feature space is of primary importance in kernel meth-  
12 ods, the reverse mapping of the obtained results from the feature space back to  
13 the input space (called the pre-image problem) is also very useful. Estimating  
14 pre-images is important in several contexts for interpretation and analysis pur-  
15 poses. From the beginning, it has been often considered to estimate denoised  
16 and compressed results of a kernel Principal Component Analysis (PCA). Other  
17 tasks are of great interest, since the pre-image estimation allows, for instance,  
18 to obtain the reverse mapping of the centroids of a kernel clustering, and of the  
19 atoms as well as of the sparse representations in kernel dictionary learning.  
20

21 In view of the importance of the pre-image estimation issue and of its bene-  
22 fits in machine learning, several major propositions have been developed. First,  
23 in Mika et al. [23], the problem is formalised as a nonlinear optimisation prob-  
24 lem and, for the particular case of the Gaussian kernel, a fixed-point iterative  
25 solution to estimate the reverse mapping is proposed. To avoid numerical insta-  
26 bilities of the latter approach, in Kwok et al.[18], the relationship between the  
27 distances in feature and input spaces is established for standard kernels, and  
28 then used to approximate pre-images by multidimensional scaling. In Bakir et  
29 al. [3], the pre-image estimation problem is cast as a regression problem be-  
30 tween the input and the mapped data, the learned regression model is then  
31 used to predict pre-images. Honeine and Richard proposed in [15] an approach  
32 where the main idea is to estimate, from the mapped data, a coordinate system  
33 that ensures an isometry with the input space; this approach has the advantage  
34 to provide a closed-form solution, to be independent of the kernel nature and  
35 to involve only linear algebra. More recently, task-specific estimation has been  
36 studied, such as the resolution of the pre-image problem for nonnegative matrix  
37 factorisation in [32].

38 All the proposed methods for pre-image estimation are either based on op-  
39 timisation schema, such as gradient descent or fixed-point iterative solution, or  
40 based on ideas borrowed from dimensionality reduction methods. In particu-  
41 lar, these methods were developed for Euclidean input spaces, as derivations  
42 are straightforward owing to linear algebra (see [16] for a survey on the resolu-  
43 tion of the pre-image problems in machine learning). A major challenge arises  
44 when dealing with non-Euclidean input spaces, that describe complex data as  
45 sequences, time series, manifolds or graphs. Some recent works address that  
46 pre-image problem on that challenging data. For instance, in Cloninger et al.  
47 [9] the pre-image problem is addressed for Laplacian Eigenmaps under  $L_1$  reg-  
48 ularisation and in Bianchi et al. [6] an encoder-decoder is used to learn a latent  
49 representation driven by the kernel similarities, where the pre-image estimation  
50 is explicitly given by the decoder side.

51 For temporal data, while kernel machinery has been increasingly investigated  
52 with success for time series analytics [13, 27, 31, 30, 29, 19], the pre-image  
53 problem for temporal data remains in its infancy. In addition, time series data,  
54 that involve varying delays and/or different lengths, are naturally lying in a  
55 non-Euclidean input space, making the above existing pre-image approaches for  
56 static data inapplicable. This work aims to fill this gap, by proposing a pre-  
57 image estimation approach for time series kernel analytics, that consists of two  
58 steps. In the first step, a time warp function, driven by distance constraints  
59 in the feature space, is defined to embed time series in a metric space where  
60 analytics can be performed conveniently. In the second step, the time series  
61 pre-image estimation is cast as learning a linear or a nonlinear transformation  
62 that ensures a local isometry between the time series embedding space and the  
63 feature space. The relevance of the proposed method is studied through three  
64 major tasks that require pre-image estimation: 1) time series averaging, 2) time  
65 series reconstruction and denoising under kernel PCA, and 3) time series repre-  
66 sentation learning and dictionary learning under kernel  $k$ -SVD. The benefits of

67 the proposed method are assessed through extensive experiments conducted on  
 68 33 publicly-available time series datasets, including univariate and multivariate  
 69 time series that may include varying delays and be of the different lengths.

70

71 The main contributions of this paper are:

- 72 1. We propose a time warp function, driven by distance constraints in the  
 73 feature space, that embeds time series into an Euclidean space
- 74 2. We cast the time series pre-image estimation approach as learning a linear  
 75 or nonlinear transformations in the feature space
- 76 3. We propose a closed-form solution for pre-image estimation by preserving  
 77 a local isometry between the temporal embedded space and the feature  
 78 space
- 79 4. We conduct wide experiments to compare the proposed approach to the  
 80 major alternative pre-image estimation methods under three crucial tasks:  
 81 1) time series averaging, 2) time series reconstruction and denoising and  
 82 3) time series representation and dictionary learning.

83 The remainder of the paper is organised as follows. Section 2 gives a brief  
 84 introduction to kernel PCA and kernel  $k$ -SVD and Section 3 presents the major  
 85 pre-image estimation methods. In Section 4, we formalise the pre-image esti-  
 86 mation problem for time series and develop the proposed solution as well as the  
 87 corresponding algorithm. We detail the experiments conducted and discuss the  
 88 obtained results in Section 5.

## 89 2. Kernel PCA and kernel $k$ -SVD

90 Kernel methods [24] rely on embedding samples  $\mathbf{x}_i \in \mathbb{R}^d$  with  $\Phi(\mathbf{x}_i)$  into a  
 91 feature space  $\mathcal{H}$ , a Hilbert space of arbitrary large and possibly infinite dimen-  
 92 sion. The map function  $\Phi$  needs not to be explicitly defined, since computations  
 93 conducted in  $\mathcal{H}$  can be carried out by a kernel function that measures the inner  
 94 product in that space, namely  $\kappa(\mathbf{x}_i, \mathbf{x}_{i'}) = \langle \Phi(\mathbf{x}_i), \Phi(\mathbf{x}_{i'}) \rangle$  for all  $\mathbf{x}_i, \mathbf{x}_{i'}$ . Given  
 95 a set of input samples  $\{\mathbf{x}_i\}_{i=1}^N$ ,  $\mathbf{x}_i \in \mathbb{R}^d$ , let  $K$  be the Gram matrix related  
 96 to the kernel, namely  $K_{ii'} = \kappa(\mathbf{x}_i, \mathbf{x}_{i'})$ . Let  $X = [\mathbf{x}_1, \dots, \mathbf{x}_N] \in \mathbb{R}^{d \times N}$  be the  
 97 description of  $N$  input samples  $\mathbf{x}_i \in \mathbb{R}^d$  and, with some abuse of notation, let  
 98  $\Phi(X)$  be the matrix of entries  $\Phi(\mathbf{x}_1), \dots, \Phi(\mathbf{x}_N)$ .

99

100 In the following, we describe two well-known kernel methods, kernel PCA  
 101 and kernel  $k$ -SVD, as nonlinear extensions of the well-known PCA and  $k$ -SVD.  
 102 While both methods estimate a linear combination for optimal reconstruction  
 103 of the input samples, the former forces the orthogonality of the atoms that leads  
 104 to an orthonormal basis, and the latter forces the sparsity while relaxing the  
 105 orthogonality condition.

### 106 2.1. Kernel PCA

107 Kernel PCA extends standard PCA to find principal components that are  
 108 nonlinearly related to the input variables. For that, the principal components

109 are rather determined in the feature space. For the sake of clarity, we assume  
 110 for now that we are dealing with centred mapped data, namely  $\sum_{i=1}^N \Phi(\mathbf{x}_i) = \mathbf{0}$ .  
 111 The covariance matrix in the feature space takes then the form

$$C = \frac{1}{N} \sum_{i=1}^N \Phi(\mathbf{x}_i) \Phi(\mathbf{x}_i)^T. \quad (1)$$

112 Similarly to standard PCA, the objective comes to find the pairs of eigenvalue  
 113  $\lambda_j \geq 0$  and corresponding eigenvector  $\mathbf{u}_j \in \mathcal{H} \setminus \mathbf{0}$  that satisfy

$$\lambda_j \mathbf{u}_j = C \mathbf{u}_j, \quad (2)$$

114 namely for each  $\Phi(\mathbf{x}_i)$

$$\lambda_j \langle \mathbf{u}_j, \Phi(\mathbf{x}_i) \rangle = \langle C \mathbf{u}_j, \Phi(\mathbf{x}_i) \rangle. \quad (3)$$

115 As each eigenvector  $\mathbf{u}_j$  lies in the span of  $\Phi(\mathbf{x}_1), \dots, \Phi(\mathbf{x}_N)$ , there exist coeffi-  
 116 cients  $\alpha_{ij}, \dots, \alpha_{Nj}$  such that

$$\mathbf{u}_j = \sum_{i=1}^N \alpha_{ij} \Phi(\mathbf{x}_i). \quad (4)$$

117 From Eq. (3) and Eq. (4), and by simple developments, the problem in Eq. (2)  
 118 remains to find the solution of the eigendecomposition problem:

$$\lambda_j \boldsymbol{\alpha}_j = \frac{1}{N} K \boldsymbol{\alpha}_j. \quad (5)$$

119 Let  $\lambda_1 \geq \dots \geq \lambda_p$  be the  $p$  highest non-zero eigenvalues of  $\frac{1}{N} K$  and  $\boldsymbol{\alpha}_1, \dots, \boldsymbol{\alpha}_p$   
 120 their corresponding eigenvectors. The principal components in the feature space  
 121 are then given by computing the projections  $P_j(\Phi(\mathbf{x}))$  of the sample  $\mathbf{x}$  onto the  
 122 eigenvector  $\mathbf{u}_j = \Phi(X) \boldsymbol{\alpha}_j$ :

$$P_j(\Phi(\mathbf{x})) = \langle \mathbf{u}_j, \Phi(\mathbf{x}) \rangle = \sum_{i=1}^N \alpha_{ij} \langle \Phi(\mathbf{x}_i), \Phi(\mathbf{x}) \rangle = \mathbf{k}_x \boldsymbol{\alpha}_j \quad (6)$$

123 with  $\mathbf{k}_x = [\kappa(\mathbf{x}_1, \mathbf{x}), \dots, \kappa(\mathbf{x}_N, \mathbf{x})]$ . By denoting  $\boldsymbol{\alpha} = [\boldsymbol{\alpha}_1, \dots, \boldsymbol{\alpha}_p]$ , the description  
 124  $P(\Phi(\mathbf{x}))$  of  $\Phi(\mathbf{x})$  into the subspace of the  $p$  first principal components is then

$$P(\Phi(\mathbf{x})) = (\mathbf{k}_x \boldsymbol{\alpha})^T \quad (7)$$

125 Two considerations should be taken. First, the eigenvector expansion coeffi-  
 126 cients  $\boldsymbol{\alpha}_j$  should be normalised by requiring  $\lambda_j \langle \boldsymbol{\alpha}_j, \boldsymbol{\alpha}_j \rangle = 1$ . Secondly, as  $\Phi(\mathbf{x}_i)$   
 127 are assumed centred, both the Gram matrix  $K$  in Eq. (5) and  $\mathbf{k}_x$  used in Eq.  
 128 (6) and Eq. (7) need to be substituted with their centred counterparts, namely

$$\tilde{K}_{ij} = (K - \mathbf{1}_N K - K \mathbf{1}_N + \mathbf{1}_N K \mathbf{1}_N)_{ij} \quad (8)$$

$$\tilde{\mathbf{k}}_x = \left( \mathbf{k}_x - \frac{1}{N} \mathbf{1}_N^T K \right) (I_N - \mathbf{1}_N) \quad (9)$$

129 with  $(\mathbf{1}_N)_{ij} = 1/N$  for all  $i, j$ ,  $I_N$  the identity matrix and  $\mathbf{1}_N \in \mathbb{R}^N$  the unit  
 130 vector.

131 *2.2. Kernel  $k$ -SVD*

132 Sparse coding and dictionary learning become popular methods for a vari-  
 133 ety of tasks as feature extraction, reconstruction, denoising, compressed sensing  
 134 and classification [17, 4, 5].  $k$ -SVD [1] is among the most-known and tractable  
 135 dictionary learning approach to learn a dictionary and to sparse represent the  
 136 input samples as a linear combination of the dictionary atoms. When deal-  
 137 ing with complex data, kernel  $k$ -SVD may be required to learn, in the feature  
 138 space, the dictionary and the sparse representations of the mapped samples as  
 139 a nonlinear combination of the dictionary atoms [28]. Let us introduce a brief  
 140 description of kernel  $k$ -SVD.

141 Let  $D = [\mathbf{d}_1, \dots, \mathbf{d}_L] \in \mathbb{R}^{d \times L}$  be the dictionary composed of  $L$  atoms  $\mathbf{d}_j \in \mathbb{R}^d$ .  
 142 The embedded dictionary  $\Phi(D) = \Phi(X)\mathcal{B}$  is defined as a linear representation  
 143 of  $\Phi(X)$ , since the atoms lie in the subspace spanned by the  $\Phi(X)$ . The kernel  
 144 dictionary learning problem takes the form  
 145

$$\min_{\mathcal{B}, \mathcal{A}} \|\Phi(X) - \Phi(X)\mathcal{B}\mathcal{A}\|_{\mathcal{F}}^2 \quad (10)$$

$$\text{s.t. } \|\mathbf{a}_i\|_0 \leq \tau \quad \forall i = 1, \dots, N, \quad (11)$$

146 where  $\|\cdot\|_{\mathcal{F}}$  is the Frobenius norm<sup>1</sup>, the matrix  $\mathcal{B} = [\boldsymbol{\beta}_1, \dots, \boldsymbol{\beta}_L] \in \mathbb{R}^{N \times L}$   
 147 gives the representation of the embedded atoms into the base  $\Phi(X)$  and  $\mathcal{A} =$   
 148  $[\mathbf{a}_1, \dots, \mathbf{a}_N] \in \mathbb{R}^{L \times N}$  gives the sparse representations of  $\Phi(X)$ , with the sparsity  
 149 level  $\tau$  imposed by the above constraint.

150 The kernel  $k$ -SVD algorithm iteratively cycles between two stages. In the  
 151 first stage, the dictionary is assumed fixed with  $\mathcal{B}$  known and a kernel orthog-  
 152 onal matching pursuit (OMP) technique [20] is deployed to estimate  $\mathcal{A}$ . As in  
 153 standard OMP, given a sample  $\mathbf{x}$ , we select the first atom that best reconstructs  
 154  $\phi(\mathbf{x})$ ; namely we select the  $j$ -th atom that maximises  
 155

$$(\mathbf{k}_{\mathbf{x}} - \mathbf{a}_{\mathbf{x}}^T \mathcal{B}^T K) \boldsymbol{\beta}_j. \quad (12)$$

156 The sparse codes are then updated by the projections onto the subspace of the  
 157 yet selected atoms

$$\mathbf{a}_{\mathbf{x}} = (\mathcal{B}_{\Omega}^T K \mathcal{B}_{\Omega})^{-1} (\mathbf{k}_{\mathbf{x}} \mathcal{B}_{\Omega})^T, \quad (13)$$

158 where  $\mathcal{B}_{\Omega}^T$  is the submatrix of  $\mathcal{B}$  limited to the yet selected atoms. The proce-  
 159 dure is reiterate until the selection of  $\tau$  atoms.

160 Once the sparse codes  $\mathcal{A}$  of the  $N$  samples estimated, the second stage of the  
 161 kernel  $k$ -SVD is performed to update both  $\mathcal{B}$  and  $\mathcal{A}$ . For that, the reconstruction  
 162

---

<sup>1</sup>  $\|M\|_{\mathcal{F}} = \sqrt{\sum_{i=1}^p \sum_{j=1}^q (m_{ij})^2}$  is the Frobenius norm of the matrix  $M \in \mathbb{R}^{p \times q}$  of general term  $m_{ij}$

163 error is defined as

$$\min_{\mathcal{B}, \mathcal{A}} \|\Phi(X) - \Phi(X) \sum_{j=1}^L \beta_j \mathbf{a}_j\|_{\mathcal{F}}^2, \quad (14)$$

164 with  $\mathbf{a}_j \in \mathbb{R}^N$  referencing the  $j$ -th row of  $\mathcal{A}$ , namely

$$\min_{\mathcal{B}, \mathcal{A}} \|\Phi(X) E_k - \Phi(X) \beta_k \mathbf{a}_k\|_{\mathcal{F}}^2, \quad (15)$$

165 with  $E_k = I_N - \sum_{j \neq k} \beta_j \mathbf{a}_j$ . the error of reconstruction matrix when removing  
166 the  $k$ -th atom. An eigendecomposition is then performed to get

$$(E_k^R)^T K(E_k^R) = V \Sigma V^T, \quad (16)$$

167 where  $E_k^R$  is the error of reconstruction restricted to the samples that have  
168 involved the  $k$ -th atom. The sparse codes  $\beta_k$  and  $\mathbf{a}_k^R$  are updated by using the  
169 first eigenvector  $\mathbf{v}_1$  with

$$\mathbf{a}_k^R = \sigma_1 \mathbf{v}_1^T \text{ and } \beta_k = \sigma_1^{-1} E_k^R \mathbf{v}_1. \quad (17)$$

### 170 3. Related works on pre-image estimation

171 From the representer theorem [22] any result  $\varphi \in \mathcal{H}$  obtained by some kernel  
172 method may be expressed in the form  $\varphi = \sum_{i=1}^N \gamma_i \Phi(\mathbf{x}_i)$ ; that is as a linear  
173 combination of the mapped training samples  $\{\Phi(\mathbf{x}_i)\}_{i=1}^N$ . In general, finding  
174 the exact pre-image  $\mathbf{x}$  such that  $\Phi(\mathbf{x}) = \varphi$  is an ill-posed problem, that is often  
175 addressed by providing an approximate solution, namely by estimating  $\mathbf{x}^*$  such  
176 that  $\Phi(\mathbf{x}^*) \approx \varphi$ . In the following, we describe three major methods to estimate  
177 the pre-image  $\mathbf{x}^*$  of a given  $\varphi \in \mathcal{H}$ .

#### 178 3.1. Pre-image estimation under distance constraints

179 The main idea proposed in Kwok et al. [18] is to use the distances between  
180  $\varphi$  and  $\Phi(\mathbf{x}_i)$  and their relation to the distances between the pre-image  $\mathbf{x}^*$  and  
181  $\mathbf{x}_i$ . The main steps of the proposed approach are:

- 182 1. Let  $\tilde{d}^2(\varphi, \Phi(\mathbf{x}_i)) = \langle \varphi, \varphi \rangle - 2\langle \varphi, \Phi(\mathbf{x}_i) \rangle + \langle \Phi(\mathbf{x}_i), \Phi(\mathbf{x}_i) \rangle$  be the square dis-  
183 tance between  $\varphi$  and any  $\Phi(\mathbf{x}_i)$ . In practice, only neighbouring elements  
184 are considered. Let  $\Phi(\hat{\mathbf{x}}_1), \dots, \Phi(\hat{\mathbf{x}}_n)$  denote the  $n$ -th closest elements to  $\varphi$ .
- 185 2. For an isotropic kernel<sup>2</sup>, the relation  $d^2(\mathbf{x}_i, \mathbf{x}_j) = g(\tilde{d}^2(\Phi(\mathbf{x}_i), \Phi(\mathbf{x}_j)))$  be-  
186 tween the distances in the input and the feature spaces can be established.

---

<sup>2</sup>an isotropic kernel is a function of the form  $k(\mathbf{x}, \mathbf{y}) = f(\|\mathbf{x} - \mathbf{y}\|)$  that depends only on the norm of the lag vector between two samples.

187 3. A solution is then deployed to determine the pre-image  $\mathbf{x}^*$  such that

$$[d^2(\mathbf{x}^*, \hat{\mathbf{x}}_1), \dots, d^2(\mathbf{x}^*, \hat{\mathbf{x}}_n)] = [g(\tilde{d}^2(\varphi, \Phi(\hat{\mathbf{x}}_1))), \dots, g(\tilde{d}^2(\varphi, \Phi(\hat{\mathbf{x}}_n)))] \quad (18)$$

188 For that, an SVD is deployed on the centred version of the submatrix  
189  $X_n = [\hat{\mathbf{x}}_1, \dots, \hat{\mathbf{x}}_n]$ , namely

$$X_n(I_n - \mathbf{1}_n) = U\Lambda V^T, \quad (19)$$

190 where  $U = [\mathbf{u}_1, \dots, \mathbf{u}_q]$  is the  $d \times q$  matrix of the left-singular vectors.  
191 Let  $Z = [\mathbf{z}_1, \dots, \mathbf{z}_n] = \Lambda V^T$  be the  $q \times n$  matrix giving the projections of  
192  $\hat{\mathbf{x}}_i$  on the  $\mathbf{u}_j$ 's orthonormal vectors. The pre-image estimation  $\mathbf{x}^*$  is then  
193 obtained as:

$$\mathbf{x}^* = U\mathbf{z}^* + \frac{1}{n}X_n\mathbf{1}_n, \quad (20)$$

194 where  $\mathbf{z}^*$ , the projection of  $\mathbf{x}^*$  on the  $[\mathbf{u}_1, \dots, \mathbf{u}_q]$  coordinate system, is

$$\mathbf{z}^* = -\frac{1}{2}(ZZ^T)^{-1}Z(\mathbf{d}^2 - \mathbf{d}_0^2), \quad (21)$$

195 with  $\mathbf{d}_0^2 = [\|\mathbf{z}_1\|^2, \dots, \|\mathbf{z}_n\|^2]^T$ ,  $\mathbf{d}^2 = [d_1^2, \dots, d_n^2]^T$  and  $d_i^2 = g(\tilde{d}^2(\varphi, \Phi(\hat{\mathbf{x}}_i)))$ .

### 196 3.2. Pre-image estimation by isometry preserving

197 To learn the pre-image  $\mathbf{x}^*$  of a given  $\varphi = \sum_{i=1}^N \gamma_i \Phi(\mathbf{x}_i)$ , the proposed  
198 approach in [15] proceeds in two steps. First, a coordinate system, spanned by  
199 the feature vectors  $\{\Phi(\mathbf{x}_i)\}_{i=1}^N$  is learned to ensure an isometry with the input  
200 space; subsequently, the coordinate system is used to estimate the pre-image  $\mathbf{x}^*$   
201 of  $\varphi$ . These two main steps are summarised in the followings:

202 1. Let  $\Psi = \{\psi_1, \dots, \psi_p\}$  ( $p \leq N$ ) be a coordinate system in the feature space,  
203 with  $\psi_k = \Phi(X)\alpha_k$ . The projection of  $\Phi(X)$  onto the coordinate system  
204 is  $P(\Phi(X)) = (KA)^T$ , where  $A = [\alpha_1, \dots, \alpha_p]$ . To estimate the coordinate  
205 system that is isometric with the input space, the following optimisation  
206 problem is solved

$$\arg \min_A \|X^T X - KAA^T K\|_{\mathcal{F}}^2 + \lambda \|KA\|_{\mathcal{F}}^2, \quad (22)$$

207 where the second term controls through the regularisation parameter  $\lambda$   
208 the smoothness of the solution. The solution of this problem satisfies  
209  $AA^T = K^{-1}(X^T X - \lambda K^{-1})K^{-1}$ .

210 2. Based on this result, the pre-image estimation  $\mathbf{x}^*$  takes the form

$$\mathbf{x}^* = \arg \min_{\mathbf{x}} \|X^T \mathbf{x} - (X^T X - \lambda K^{-1})\boldsymbol{\gamma}\|_{\mathcal{F}}^2 \quad (23)$$

211 with  $\boldsymbol{\gamma} = (\gamma_1, \dots, \gamma_N)^T$ . This problem defines a standard overdetermined  
212 equation system ( $N \gg d$ ) that can be resolved as a least-square min-  
213 imisation problem (i.e., any technique such as the pseudo-inverse or the  
214 eigendecomposition). The pre-image estimation is then:

$$\mathbf{x}^* = (XX^T)^{-1}X(X^T X - \lambda K^{-1})\boldsymbol{\gamma}. \quad (24)$$

215 *3.3. Pre-image estimation by kernel regression*

216 In Bakir et al. [3], the pre-image estimation consists in learning a kernel  
 217 regression function that maps all the  $\Phi(\mathbf{x}_i)$  in the feature space  $\mathcal{H}$  (related to  
 218 the kernel  $\kappa$ ) to  $\mathbf{x}_i$  in the input space  $\mathbb{R}^d$ . For that, first a kernel PCA is deployed  
 219 to embed  $\Phi(X)$  into the subspace spanned by the eigenvectors  $\mathbf{u}_1, \dots, \mathbf{u}_p$  defined  
 220 in (4), with  $\mathbf{u}_j = \Phi(X)\boldsymbol{\alpha}_j$ . Then, a kernel regression is learned from the set of  
 221 the projections onto the kernel PCA subspace and  $X$  as

$$\arg \min_B \|X - B\widehat{K}\|_{\mathcal{F}}^2 + \lambda\|B\|_{\mathcal{F}}^2, \quad (25)$$

222 where  $B \in \mathbb{R}^{d \times N}$  is the regression coefficient matrix and  $\widehat{K}$  is the Gram matrix  
 223 with entries  $\widehat{K}_{ij} = \widehat{\kappa}(P(\Phi(\mathbf{x}_i)), P(\Phi(\mathbf{x}_j)))$ . The solution to the problem (25) is  
 224 then

$$B = X\widehat{K}(\widehat{K}^2 + \lambda I_N)^{-1} \quad (26)$$

225 For a given result  $\boldsymbol{\varphi} = \Phi(X)\boldsymbol{\gamma} \in \mathcal{H}$ , its pre-image  $\mathbf{x}^*$  is then estimated as:

$$\mathbf{x}^* = B\widehat{\mathbf{k}}_{P(\boldsymbol{\varphi})}^T, \quad (27)$$

226 with

$$\widehat{\mathbf{k}}_{P(\boldsymbol{\varphi})} = [\widehat{\kappa}(P(\boldsymbol{\varphi}), P(\Phi(\mathbf{x}_1))), \dots, \widehat{\kappa}(P(\boldsymbol{\varphi}), P(\Phi(\mathbf{x}_N)))], \quad (28)$$

227 where  $\widehat{\kappa}(P(\boldsymbol{\varphi}), P(\Phi(\mathbf{x}_i))) = \widehat{\kappa}(\boldsymbol{\alpha}^T K \boldsymbol{\gamma}, \boldsymbol{\alpha}^T \mathbf{k}_{\mathbf{x}_i}^T)$  and  $\boldsymbol{\alpha} = [\boldsymbol{\alpha}_1, \dots, \boldsymbol{\alpha}_p]$ .

229 *3.4. Overview*

230 To sum up, the three major methods presented above define three different  
 231 approaches for pre-image estimation problem. First of all, all the methods in-  
 232 volve only linear algebra and propose solutions that don't suffer from numerical  
 233 instabilities. In Kwok et al. [18], the solution is mainly requiring the definition  
 234 of a relation between the distances into the input and the kernel feature spaces.  
 235 That requirement limite the Kwok et al. [18] approach to linear or isotropic  
 236 kernels. Honeine et al. [15] alleviate that point by proposing a closed-form solu-  
 237 tion that is applicable to any type of kernels. Furthermore, while in Honeine et  
 238 al. [15] the pre-image estimation is obtained by learning a linear transformation  
 239 into the feature space that preserves the isometry between the input and the  
 240 feature space, in Bakir et al. [3], the pre-image estimation is obtained by using  
 241 a non linear kernel regression that predicts the input samples from their images  
 242 into the feature space. Finally, while both [15] and [3] proposals involve the  
 243 whole training samples for pre-image estimation, Kwok et al. [18] uses only the  
 244 samples on the neighborhood of  $\boldsymbol{\varphi}$ , which offers a significant speed-up; highly  
 245 valuable in the case of large scale data.

246 **4. Proposed pre-image estimation for time series kernel analytics**

247 Let  $\{\mathbf{x}_i\}_{i=1}^N$  be a set of  $N$  time series, where each  $\mathbf{x}_i \in \mathbb{R}^{d \times t_i}$  is a mul-  
 248 tivariate time series of length  $t_i$  that may involve varying delays. Let  $\Phi(\mathbf{x}_i)$   
 249 be the  $\Phi$ -mapping of the time series  $\mathbf{x}_i$  into the Hilbert space  $\mathcal{H}$  related to a  
 250 temporal kernel  $\kappa$  that involves dynamic time alignments such as DTAK [25],  
 251 KDTW [2] and KGA [10]. Let  $K$  be a the corresponding Gram matrix, with  
 252 entries  $K_{ii'} = \kappa(\mathbf{x}_i, \mathbf{x}_{i'})$ . Given  $\varphi = \sum_{i=1}^N \gamma_i \Phi(\mathbf{x}_i)$  a result generated in  $\mathcal{H}$ ,  
 253 the objective is to estimate the time series  $\mathbf{x}^* \in \mathbb{R}^{d \times t^*}$  that is the pre-image  
 254 of  $\varphi$ . This problem is particularly challenging since, under varying delays, the  
 255 time series are not longer lying in a metric space, which makes inapplicable the  
 256 related work on pre-image estimation.

257 We tackle this problem in two parts. In the first part, we formalise the  
 258 pre-image estimation problem as the estimation of a linear transformation in  
 259 the feature space, that ensures an isometry between the input and the feature  
 260 spaces. Moreover, this result is extended to the estimation of a nonlinear trans-  
 261 formation in the feature space, shown powerful on challenging data in Section  
 262 5. Subsequently, we propose a local time-warp mapping function to embed  
 263 time series into a vector space where the pre-image estimation can be estimated  
 264 conveniently.  
 265

266 *4.1. Learning linear and nonlinear transformations for pre-image estimation*

267 Let  $X = [\mathbf{x}_1, \dots, \mathbf{x}_N] \in \mathbb{R}^{t \times N}$  be a matrix giving the description of  $N$  univari-  
 268 ate<sup>3</sup> time series  $\mathbf{x}_i$  that we assume first lying in the metric space  $\mathbb{R}^t$ ; Section 4.2  
 269 addresses the general case of time series that are lying into nonEuclidean space.  
 270 The proposed pre-image method relies on learning a linear transformation  $R$   
 271 in the feature space that ensures an isometry between  $X$  and  $\Phi(X)$ . We first  
 272 describe the method as a linear transformation, and then extend it to nonlinear  
 273 transformations.

274 *Linear transformation*

275 The main idea to solve the pre-image problem is the isometry preserving,  
 276 in the same spirit as the method described in Section 3.2. For this purpose,  
 277 we formalise the pre-image problem as the estimation of the square matrix  $R$   
 278 that establishes an isometry between  $X$  and  $\Phi(X)$ , by solving the optimisation  
 279 problem

$$R^* = \arg \min_R \|X^T X - \Phi(X)^T R \Phi(X)\|_{\mathcal{F}}^2. \quad (29)$$

280 By using a kernel PCA where a relevant subspace is considered, an explicit de-  
 281 scription  $P(\Phi(X)) \in \mathbb{R}^{p \times N}$  of  $\Phi(X)$  is given and Eq. (29) can thus be rewritten

---

<sup>3</sup>For multivariate time series, simply define  $X \in \mathbb{R}^{d \times t \times N}$ .

282 as:

$$R^* = \arg \min_R \|X^T X - P(\Phi(X))^T R P(\Phi(X))\|_{\mathcal{F}}^2. \quad (30)$$

283 As  $P(\Phi(X))P(\Phi(X))^T$  is invertible, a closed-form solution is given by:

$$R^* = (P(\Phi(X))P(\Phi(X))^T)^{-1} P(\Phi(X))X^T X P(\Phi(X))^T (P(\Phi(X))P(\Phi(X))^T)^{-1}. \quad (31)$$

284 The estimation of the time series  $\mathbf{x}^*$ , as the pre-image of  $\varphi = \Phi(X)\gamma$ , is then  
285 given by:

$$\begin{aligned} \mathbf{x}^* &= (XX^T)^{-1} X P(\Phi(X))^T R^* P(\varphi) \\ &= (XX^T)^{-1} X P(\Phi(X))^T R^* \alpha^T K \gamma, \end{aligned} \quad (32)$$

286 with  $P(\varphi) = \alpha^T K \gamma$  and  $\alpha$  defined in Eq. (7).

287

288 One can easily include some regularisation terms in the optimisation prob-  
289 lems (29) and (30), which can be easily propagated to the pre-image expression.  
290 For example, in the case of non-invertible  $XX^T$ , a regularisation term is intro-  
291 duced in Eq. (32) as:

$$\mathbf{x}^* = (XX^T + \lambda I_t)^{-1} X P(\Phi(X))^T R^* \alpha^T K \gamma, \quad (33)$$

292 for some positive regularisation parameter  $\lambda$ .

293 *Nonlinear transformation*

294 In the following, we propose to extend the above result to learn nonlinear  
295 transformations for pre-image estimation. Let  $\hat{\kappa}$  be a kernel defined on the  
296 feature space  $\mathcal{H}$ , and  $\hat{\Phi}$  the corresponding embedding function that maps any  
297 element of  $\mathcal{H}$  into the Hilbert space defined by  $\hat{\kappa}$ . With some abuse of notation,  
298 we denote  $\hat{\Phi}(\Phi(X))$  the matrix of all mapped elements  $\hat{\Phi}(\Phi(\mathbf{x}_i))$ , for  $i = 1, \dots, N$ .  
299 Let  $\hat{K}$  be the Gram matrix of general term  $\hat{\kappa}(\Phi(\mathbf{x}_i), \Phi(\mathbf{x}_j))$ .

300

301 The pre-image estimation problem can be then defined as learning a nonlin-  
302 ear transformation that defines an isometry between  $X$  and  $\hat{\Phi}(\Phi(X))$  as:

$$R^* = \arg \min_R \|X^T X - \hat{\Phi}(\Phi(X))^T R \hat{\Phi}(\Phi(X))\|_{\mathcal{F}}^2. \quad (34)$$

303 Similarly, a closed-form solution for  $R^*$  can be obtained as:

$$\begin{aligned} R^* &= (P(\hat{\Phi}(\Phi(X)))P(\hat{\Phi}(\Phi(X)))^T)^{-1} P(\hat{\Phi}(\Phi(X))) \\ &\quad X^T X P(\hat{\Phi}(\Phi(X)))^T (P(\hat{\Phi}(\Phi(X)))P(\hat{\Phi}(\Phi(X)))^T)^{-1}, \end{aligned} \quad (35)$$

304 and

$$P(\hat{\Phi}(\Phi(X))) = \hat{\alpha}^T \hat{K}. \quad (36)$$

305 To estimate  $\widehat{K}$ , an indirect manner is to use a kernel PCA, with  $\widehat{\kappa}(\Phi(\mathbf{x}_i), \Phi(\mathbf{x}_j)) \approx$   
 306  $\widehat{\kappa}(P(\Phi(\mathbf{x}_i)), P(\Phi(\mathbf{x}_j)))$ . A simpler way is possible when dealing with kernels  
 307 that are radial basis functions. For example, for the well-known Gaussian ker-  
 308 nel  $\widehat{\kappa}$ ,  $\widehat{K}$  is estimated directly from  $K$  as:

$$\begin{aligned} \widehat{\kappa}(\Phi(\mathbf{x}_i), \Phi(\mathbf{x}_j)) &= \exp\left(-\frac{\|\Phi(\mathbf{x}_i) - \Phi(\mathbf{x}_j)\|^2}{2\sigma^2}\right) \\ &= \exp\left(-\frac{\langle\Phi(\mathbf{x}_i), \Phi(\mathbf{x}_i)\rangle - 2\langle\Phi(\mathbf{x}_i), \Phi(\mathbf{x}_j)\rangle + \langle\Phi(\mathbf{x}_j), \Phi(\mathbf{x}_j)\rangle}{2\sigma^2}\right) \\ &= \exp\left(-\frac{\kappa(\mathbf{x}_i, \mathbf{x}_i) - 2\kappa(\mathbf{x}_i, \mathbf{x}_j) + \kappa(\mathbf{x}_j, \mathbf{x}_j)}{2\sigma^2}\right) \end{aligned} \quad (37)$$

309 The estimation of the pre-image of  $\varphi = \sum_{i=1}^N \gamma_i \Phi(\mathbf{x}_i)$  is then given by the  
 310 time series  $\mathbf{x}^*$ :

$$\mathbf{x}^* = (XX^T)^{-1} X P(\widehat{\Phi}(\Phi(X)))^T R^* P(\widehat{\Phi}(\varphi)), \quad (38)$$

311 with  $P(\widehat{\Phi}(\varphi)) = (\widehat{\mathbf{k}}_\varphi \widehat{\alpha})^T$ , where  $\widehat{\mathbf{k}}_\varphi$  is the vector whose  $i$ -th entry is

$$\widehat{\kappa}(\varphi, \Phi(\mathbf{x}_i)) = \exp\left(-\frac{\gamma^T K \gamma - 2\gamma^T \mathbf{k}_{\mathbf{x}_i}^T + K_{ii}}{2\sigma^2}\right). \quad (39)$$

312 The above proposed formulations and results for pre-image estimation (Sec-  
 313 tion 4.1) present some similarities and differences with the method proposed  
 314 in [16] and presented in Section 3.2. First of all, both approaches propose for-  
 315 mulations and solutions that only require linear algebra and are independent  
 316 of the type of kernel. To establish the isometry, in [16] a linear transforma-  
 317 tion restricted to the form  $R = \Phi(X)AA^T\Phi(X)^T$  is estimated, whereas in our  
 318 proposal the estimated  $R$  may be linear Eq.(30) or non linear Eq.(34) and is im-  
 319 portantly unconstrained, namely of general form which enlarges its potential to  
 320 deal with complex structures. Finally, while in [16] the solution Eq.(24) involves  
 321 the kernel information through the regularisation term, which may be canceled  
 322 for lower values of  $\lambda$ , in the proposed solutions Eq.(33) and Eq.(38) the kernel  
 323 information is entirely considered regardless of the regularisation specifications.

324

#### 325 4.2. Learning a metric space embedding for time series pre-image estimation

326 In Section 4.1, time series are assumed of the same length and lying in a met-  
 327 ric space. However, in general  $X = \{\mathbf{x}_i\}_{i=1}^N$  is instead composed of time series  
 328  $\mathbf{x}_i$  of different lengths  $t_i$  that are located in a non-metric space, rendering the  
 329 previous results as well as the pre-image estimation related works not applicable.

330

331 To address the pre-image estimation for such challenging time series, we de-  
 332 fine an embedding function that allows to represent the time series in a metric

333 space, where the previous linear and nonlinear transformations method for pre-  
 334 image estimation can be performed conveniently.

335  
 336 For this purpose, first we define  $\mathcal{N}_\varphi$  in  $\mathcal{H}$  and  $\mathcal{N}_\varphi^{-1}$  as the set of the  $n$ -closest  
 337 neighbours of  $\varphi$  and its pre-image, given as:

$$\begin{aligned} \mathcal{N}_\varphi &= \left\{ \Phi(\mathbf{x}_i) \mid \langle \Phi(\mathbf{x}_i), \varphi \rangle = \sum_{j=1}^N \gamma_j \kappa(\mathbf{x}_i, \mathbf{x}_j) \text{ is among the } n \text{ highest values} \right\}, (40) \\ \mathcal{N}_\varphi^{-1} &= \{ \mathbf{x}_i \mid \Phi(\mathbf{x}_i) \in \mathcal{N}_\varphi \} \end{aligned} \quad (41)$$

338 Let  $\Phi(\mathbf{x}_r)$  be the representative of  $\mathcal{N}_\varphi$  with  $\mathbf{x}_r \in \mathbb{R}^{t^*}$  defined as:

$$\Phi(\mathbf{x}_r) = \arg \max_{\Phi(\mathbf{x}_i) \in \mathcal{N}_\varphi} \sum_{\Phi(\mathbf{x}_j) \in \mathcal{N}_\varphi} \kappa(\mathbf{x}_i, \mathbf{x}_j). \quad (42)$$

To resorb the arising delays, a temporal alignment between each  $\mathbf{x}_i$  and  $\mathbf{x}_r$  is then performed by dynamic programming. An alignment  $\boldsymbol{\pi}$  of length  $|\boldsymbol{\pi}| = m$  between  $\mathbf{x}_i$  and  $\mathbf{x}_r$  is defined as the set of  $m$  increasing couples

$$\boldsymbol{\pi} = ((\pi_1(1), \pi_2(1)), (\pi_1(2), \pi_2(2)), \dots, (\pi_1(m), \pi_2(m))),$$

339 where the applications  $\pi_1$  and  $\pi_2$  defined from  $\{1, \dots, m\}$  to  $\{1, \dots, t_i\}$  and  $\{1, \dots, t^*\}$   
 340 respectively obey to the following boundary and monotonicity conditions:

$$\begin{aligned} 341 \quad & 1 = \pi_1(1) \leq \pi_1(2) \leq \dots \leq \pi_1(m) = t_i \\ 342 \quad & 1 = \pi_2(1) \leq \pi_2(2) \leq \dots \leq \pi_2(m) = t^* \end{aligned}$$

343 and  $\forall l \in \{1, \dots, m\}$ ,  $\pi_1(l+1) \leq \pi_1(l) + 1$  and  $\pi_2(l+1) \leq \pi_2(l) + 1$ ,  $(\pi_1(l+1) -$   
 344  $\pi_1(l)) + (\pi_2(l+1) - \pi_2(l)) \geq 1$ .

345  
 346 Intuitively, an alignment  $\boldsymbol{\pi}$  between  $\mathbf{x}_i$  and  $\mathbf{x}_r$  describes a way to associate  
 347 each element of  $\mathbf{x}_i$  to one or more elements of  $\mathbf{x}_r$  and vice-versa. Such an  
 348 alignment can be conveniently represented by a path in the  $t_i \times t^*$  grid, as  
 349 shown in Figure 1 (left), where the above monotonicity conditions ensure that  
 350 the path is neither going back nor jumping. The optimal alignment  $\boldsymbol{\pi}^*$  between  
 351  $\mathbf{x}_i$  and  $\mathbf{x}_r$  is then obtained as:

$$\boldsymbol{\pi}^* = \arg \min_{\boldsymbol{\pi}=(\pi_1, \pi_2)} \|\mathbf{x}_i^{\pi_1} - \mathbf{x}_r^{\pi_2}\|^2 \quad (43)$$

352 where  $\mathbf{x}_i^{\pi_1} = (x_{i \pi_1(1)}, \dots, x_{i \pi_1(m)})$  and  $\mathbf{x}_r^{\pi_2} = (x_{r \pi_2(1)}, \dots, x_{r \pi_2(m)})$  are  $\mathbf{x}_i$  and  
 353  $\mathbf{x}_r$  aligned through  $\boldsymbol{\pi}$ .

354  
 355 We define  $f_r$ , the temporal embedding function, to embed time series  $\mathbf{x}_i \in$   
 356  $\mathbb{R}^{d \times t_i}$  into a new temporal metric space as:

$$\begin{aligned} f_r : \quad X &\longrightarrow \tilde{X} \subset \tilde{\mathcal{I}} = \mathbb{R}^{d \times t^*} \\ \mathbf{x}_i &\longrightarrow f_r(\mathbf{x}_i) = \mathbf{x}_i W_{ir} N_{ir} \end{aligned} \quad (44)$$

357 where  $W_{ir} \in \{0, 1\}^{t_i \times t^*}$  is the binary matrix related to the optimal tempo-  
 358 ral alignment between  $\mathbf{x}_i$  and  $\mathbf{x}_r$ , as shown in Figure 1 (right). The matrix

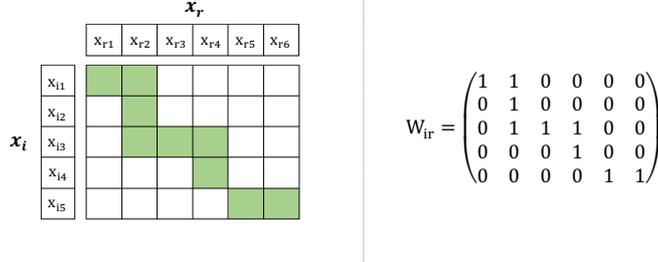


Figure 1: In the left, the temporal alignment between  $\mathbf{x}_i$  ( $t_i = 5$ ) and  $\mathbf{x}_r$  ( $t^* = 6$ ), the optimal alignment  $\pi^*$  is indicated in green. In the right, the adjacency binary matrix related to the optimal temporal alignment.

359  $N_{ir} = \text{diag}(W_{ir}^T \mathbf{1}_{t_i})^{-1}$  is the weight diagonal matrix of order  $t^*$ , of general term  
360  $\frac{1}{|N_t|}$ , that gives the weight of the element  $t$  of  $\mathbf{x}_r$ , where  $|N_t|$  is the number of  
361 time stamps of  $\mathbf{x}_i$  aligned to  $t$ . In particular, note that  $\mathbf{x}_r$  remains unchanged  
362 by  $f_r$ , as  $W_{rr} = N_{rr} = \text{diag}([1, 1, \dots, 1])$ .

363  
364 The set of embedded time series  $\tilde{X} = \{f_r(\mathbf{x}_1), \dots, f_r(\mathbf{x}_N)\}$  is for now lying  
365 in a metric space  $\tilde{\mathcal{I}}$ , where the delays are resorbed w.r.t. the representative  
366 time series  $\mathbf{x}_r$ . The pre-image solution provided in the method described in  
367 Section 4.1 can be developed to establish a linear or nonlinear transformations  
368 to preserve an isometry between  $\tilde{X}$  and  $\Phi(X)$ . The algorithm for the proposed  
369 solution TSPRIMA is summarised in Algorithm 1.

---

**Algorithm 1** TSPRIMA: Pre-image estimation for time series

---

- 1: **Input:**  $\{\mathbf{x}_i\}_{i=1}^N$  with  $\mathbf{x}_i \in \mathbb{R}^{d \times t_i}$ ,  $\kappa$  (a temporal kernel),  $\hat{\kappa}$  (a Gaussian kernel),
  - 2:  $\gamma$  (with  $\varphi = \sum_{i=1}^N \gamma_i \Phi(\mathbf{x}_i)$ ),  $n$  (the neighbourhood size)
  - 3: **Output:**  $\mathbf{x}^*$  the pre-image estimation of  $\varphi$
  - 4:
  - 5: Define  $\mathcal{N}_\varphi$ ,  $\mathcal{N}_\varphi^{-1}$  and  $\mathbf{x}_r$  using respectively (40), (41) and (42)
  - 6: Embed  $\mathcal{N}_\varphi^{-1}$  into a temporal metric space by using Eq. (44), set  $\tilde{N}_\varphi^{-1} = f_r(\mathcal{N}_\varphi^{-1})$
  - 7: Set  $X = \tilde{N}_\varphi^{-1}$  and  $\Phi(X) = \mathcal{N}_\varphi$
  - 8: Learn a linear (resp. nonlinear) transformation  $R$  by using Eq. (31) (resp. Eq. (35))
  - 9: Estimate the pre-image  $\mathbf{x}^*$  based on a linear (resp. nonlinear) transformation using Eq. (33) (resp. Eq. (38))
-

370 **5. Experiments**

371 In this section, we evaluate the efficiency of the proposed pre-image esti-  
 372 mation method under three major time series analysis tasks: 1) time series  
 373 averaging, 2) time series reconstruction and denoising and 3) time series rep-  
 374 resentation learning. The proposed pre-image estimation method TsPRIMA is  
 375 compared to three major alternative approaches introduced in Section 3, and  
 376 referenced in the following as Honeine, Kwok and Bakir methods. The exper-  
 377 iments are conducted on 33 public datasets (Table 1) including univariate and  
 378 multivariate time series data, that may involve varying delays and be of the  
 379 same or different lengths. The 25 first datasets in Table 1 are selected from the  
 380 archive given in [8, 11] by using three selection criteria: a) have a reasonable  
 381 number of classes (Nb. of Classes < 50), b) have a sufficient size for train and  
 382 test samples (Train size <= 500 and Test size < 3000), c) avoid time series of  
 383 extra large lengths (Time series length < 700). To obtain a manageable number  
 384 of datasets, the 3 above selection criteria are applied on the top 40 datasets, in  
 385 the order set out in [8]. The 25 obtained datasets are composed of univariate  
 386 time series and half of the datasets include significant delays. We consider a  
 387 dataset as including significant delays if the difference between the 1-NN Eu-  
 388 clidean distance error and the 1-NN Dynamic time warping [21] error is greater  
 389 than 5%. The 5 next datasets include univariate and multivariate time series  
 390 covering local and noisy salient events as described in [30, 27, 14] and the three  
 391 last datasets are related to handwritten digits and characters, they are described  
 392 as multivariate time series of variable lengths [7]. In the following, we detail the  
 393 evaluation process of the pre-image estimation methods then give and discuss  
 394 the obtained results.

395 *5.1. Time series averaging*

396 Estimating the centroid of a set of time series is a major topic for many time  
 397 series analytics as summarisation, prototype extraction or clustering. Time se-  
 398 ries averaging has been an active area in the last decade, where the propositions  
 399 mainly focus on tackling the tricky problem of multiple temporal alignments  
 400 [14, 26, 27]. A suitable way to circumvent the problem of multiple temporal  
 401 alignments is to use a temporal kernel method to evaluate the time series cen-  
 402 troid in the feature space. The pre-image of the centroid is then estimated to  
 403 obtain the time series averaging in the input space.

404  
 405 In that context, let  $\{\mathbf{x}_i\}_{i=1}^N$  and  $\{\Phi(\mathbf{x}_i)\}_{i=1}^N$  be, respectively, a set of time  
 406 series and their mapped images into the Hilbert space  $\mathcal{H}$  related to the temporal  
 407 kernel DTAK [25]. Let  $\varphi = \frac{1}{N} \sum_{i=1}^N \Phi(\mathbf{x}_i)$  be the centroid of the mapped time  
 408 series in the feature space and  $\mathbf{x}^*$  its pre-image in the input space. The quality  
 409 of the obtained centroids is given by the within-class similarity  $\sum_i \text{DTAK}(\mathbf{x}^*, \mathbf{x}_i)$ ;  
 410 the higher the within-class similarity, the better is the estimated centroid.

411  
 412 To evaluate the efficiency of each pre-image estimation method, the time  
 413 series centroid is estimated for each class of the studied datasets and the induced

Table 1: Data Description

Dataset	Nb. Classes	Train size	Test size	Time series length	Univariate
CC	6	300	300	60	✓
GunPoint	2	50	150	150	✓
CBF	3	30	900	128	✓
OSULeaf	6	200	242	427	✓
SwedishLeaf	15	500	625	128	✓
Trace	4	100	100	275	✓
FaceFour	4	24	88	350	✓
Lighting2	2	60	61	637	✓
Lighting7	7	70	73	319	✓
ECG200	2	100	100	96	✓
Adiac	37	390	391	176	✓
FISH	7	175	175	463	✓
Beef	5	30	30	470	✓
Coffee	2	28	28	286	✓
OliveOil	4	30	30	570	✓
DiatomSizeR	4	16	306	345	✓
ECG5Days	2	23	861	136	✓
FacesUCR	14	200	2050	131	✓
ItalyPowerD	2	67	1029	24	✓
MedicalImages	10	381	760	99	✓
MoteStrain	2	20	1252	84	✓
SonyAIBOII	2	27	953	65	✓
SonyAIBO	2	20	601	70	✓
Symbols	6	25	995	398	✓
TwoLeadECG	2	23	1139	82	✓
SPIRAL1	1	50	50	101	✗
SPIRAL2	1	50	50	300	✗
PowerCons	2	73	292	144	✓
BME	3	30	150	128	✓
UMD	3	36	144	150	✓
DIGITS	10	100	100	29~218	✗
LOWER	26	130	260	27~163	✗
UPPER	26	130	260	27~412	✗

414 within-class similarity is evaluated. The average within-class similarity is then  
415 reported in Table 2 for each dataset and each pre-image estimation method; the  
416 best values are indicated in bold (t-test at 5% risk). In addition, a Nemenyi  
417 test [12] is performed to compare the significance of the obtained results, with  
418 the related critical difference diagram given in Figure 2. The estimated time  
419 series centroids for some challenging classes are shown in Figure 3, where we  
420 retain particularly SPIRAL1 and the handwritten digits and characters datasets

421 (DIGITS, LOWER and UPPER) as they are more intuitive to visually evaluate the  
 422 quality of the estimated time series centroids.

Table 2: Average within-class similarity of the estimated time series centroids

DataSet	TsPRIMA	Honeine	Kwok	Bakir
CC	<b>0.744</b>	0.709	0.721	0.709
GunPoint	0.902	<b>0.910</b>	0.882	0.886
CBF	<b>0.798</b>	0.737	0.755	0.737
OSULeaf	0.985	<b>0.987</b>	0.986	<b>0.987</b>
SwedishLeaf	0.910	<b>0.920</b>	<b>0.920</b>	<b>0.920</b>
Trace	<b>0.998</b>	0.992	0.991	0.992
FaceFour	<b>0.981</b>	0.980	<b>0.981</b>	0.98
Lighting2	<b>0.918</b>	0.876	0.859	0.875
Lighting7	<b>0.964</b>	0.930	0.930	0.931
ECG200	<b>0.593</b>	0.565	0.567	0.566
Adiac	<b>0.997</b>	<b>0.997</b>	0.996	<b>0.997</b>
FISH	<b>0.996</b>	0.995	0.994	0.995
Beef	<b>0.900</b>	0.892	0.898	0.890
Coffee	<b>0.998</b>	<b>0.998</b>	<b>0.998</b>	<b>0.998</b>
OliveOil	<b>0.999</b>	<b>0.999</b>	0.998	<b>0.999</b>
DiatomSizeR	<b>0.997</b>	<b>0.997</b>	<b>0.997</b>	<b>0.997</b>
ECG5Days	<b>0.777</b>	0.746	0.417	0.746
FacesUCR	<b>0.721</b>	0.699	0.648	0.700
ItalyPowerD	<b>0.610</b>	0.552	0.420	0.542
MedicalImages	<b>0.671</b>	0.644	0.637	0.646
MoteStrain	0.776	<b>0.777</b>	0.701	<b>0.777</b>
SonyAIBOII	<b>0.749</b>	0.740	0.716	0.740
SonyAIBO	0.960	<b>0.962</b>	0.955	<b>0.962</b>
Symbols	<b>0.959</b>	0.949	0.904	0.951
TwoLeadECG	<b>0.980</b>	0.977	0.911	0.977
SPIRAL1	<b>0.831</b>	0.823	0.799	0.824
SPIRAL2	<b>0.947</b>	0.940	0.934	0.940
PowerCons	<b>0.458</b>	0.328	0.436	0.330
BME	<b>0.701</b>	0.572	0.638	0.555
UMD	<b>0.800</b>	0.765	0.724	0.755
DIGITS	<b>0.746</b>	0.575	0.657	0.581
LOWER	<b>0.713</b>	0.544	0.645	0.545
UPPER	<b>0.764</b>	0.572	0.570	0.573
Nb. Best	<b>28</b>	9	4	8
Avg. Rank	<b>1.5</b>	2.68	3.24	2.58

423 *5.2. Time series reconstruction and denoising*

424 The reconstruction and denoising tasks represent a standard application con-  
 425 text for pre-image estimation. For the time series reconstruction task, a kernel

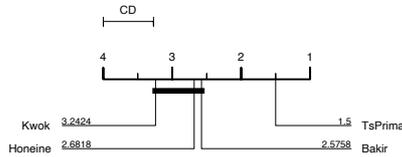


Figure 2: Nemenyi test: comparison of pre-image methods under centroid estimation task

426 PCA is performed on the training set, the reconstruction of a given test sample  
 427  $\mathbf{x}$  is then defined as the pre-image  $\mathbf{x}^*$  of its kernel PCA projection  $P(\Phi(\mathbf{x}))$ .  
 428 The latter takes the form  $\boldsymbol{\varphi} = \Phi(X)\boldsymbol{\gamma}$ , with  $\boldsymbol{\gamma}$  defined as:

$$\boldsymbol{\gamma} = (I_N - \mathbf{1}_N) \boldsymbol{\alpha} \boldsymbol{\alpha}^T \tilde{\mathbf{k}}_{\mathbf{x}} + \frac{1}{N} \mathbf{1}_N \quad (45)$$

429 The quality of the reconstruction is then measured as the similarity  $\text{DTAK}(\mathbf{x}^*, \mathbf{x})$   
 430 between each test sample  $\mathbf{x}$  and its reconstruction  $\mathbf{x}^*$ ; the higher the criterion,  
 431 the better is the reconstruction. Table 3 gives the average quality of recon-  
 432 struction obtained for each dataset and each method. Figure 4 gives the critical  
 433 difference diagram related to the Nemenyi test for the average ranking compar-  
 434 ison of the studied methods. Figure 5 shows the reconstructions obtained for  
 435 some challenging time series of DIGITS, LOWER and UPPER datasets.

436  
 437 For the time series denoising task, first a kernel PCA is performed on the  
 438 training set, then a  $(0, \sigma^2)$  Gaussian noise is added to the test samples  $\mathbf{x}$  to  
 439 generate noisy samples  $\tilde{\mathbf{x}}$  with different variances  $\sigma^2$ . The denoised sample is  
 440 obtained as the pre-image  $\mathbf{x}^*$  of its kernel PCA projection  $P(\Phi(\tilde{\mathbf{x}}))$ , with  $\boldsymbol{\gamma}$   
 441 defined as in Eq. (45). Similarly, the quality of the denoising is measured as the  
 442 similarity  $\text{DTAK}(\mathbf{x}^*, \mathbf{x})$  between  $\mathbf{x}^*$  and the initial  $\mathbf{x}$ . Table 4 gives, for different  
 443 values of  $\sigma^2$ , the average quality of the denoising for some datasets. Figure 6  
 444 illustrates the denoising results for some challenging times series of the noisy  
 445 SPIRAL2 data and of the class “M” of UPPER dataset.

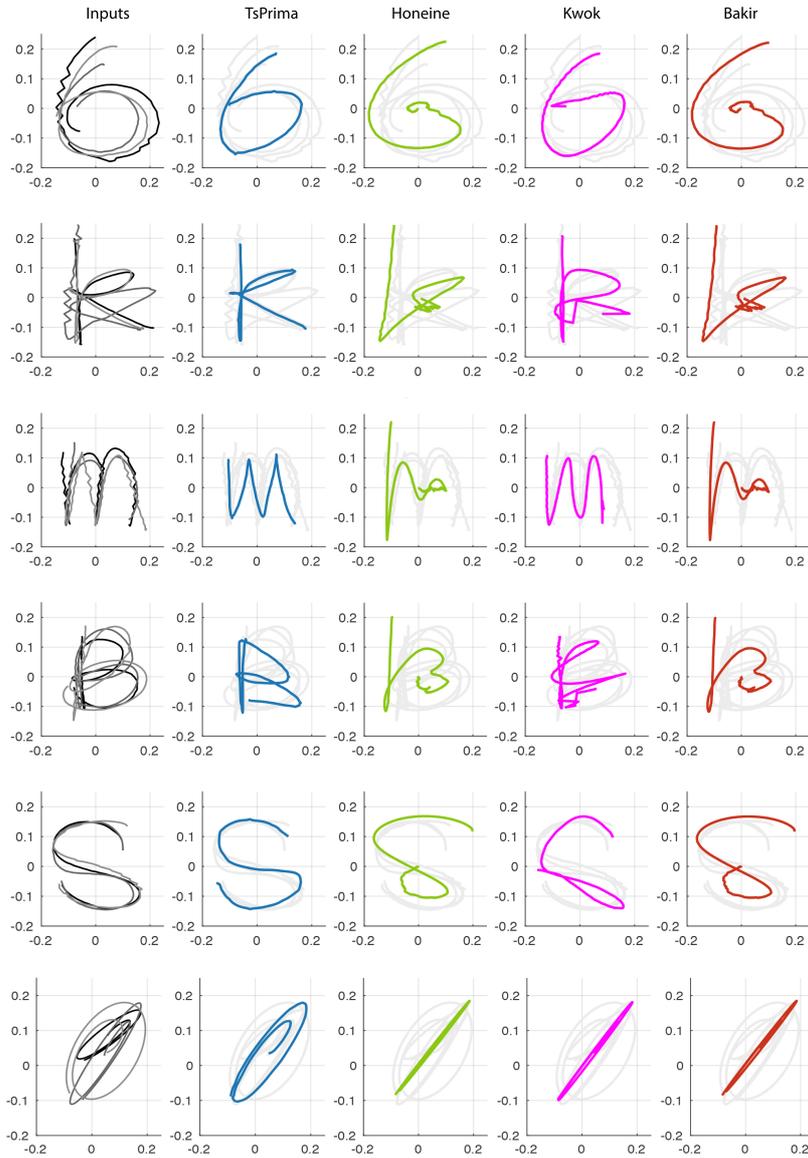


Figure 3: Time series centroids for some challenging classes of DIGITS, LOWER, UPPER and SPIRAL1 datasets

Table 3: Quality of the time series reconstruction under kernel PCA

DataSet	TSPRIMA	Honeine	Kwok	Bakir
CC	<b>0.798</b>	0.747	0.758	0.747
GunPoint	0.994	<b>0.996</b>	0.992	0.990
CBF	<b>0.916</b>	0.854	0.896	0.875
OSULeaf	0.997	<b>0.998</b>	0.995	<b>0.998</b>
SwedishLeaf	<b>0.798</b>	0.701	0.690	0.650
Trace	<b>0.689</b>	0.519	0.597	0.519
FaceFour	<b>0.981</b>	0.951	0.967	0.964
Lighting2	<b>0.993</b>	0.967	0.984	0.975
Lighting7	<b>0.954</b>	0.920	0.938	0.922
ECG200	0.965	<b>0.979</b>	0.959	0.962
Adiac	<b>0.194</b>	0.127	0.139	0.125
FISH	<b>0.779</b>	0.580	0.586	0.579
Beef	0.528	0.703	0.643	<b>0.704</b>
Coffee	0.584	<b>0.595</b>	0.570	0.559
OliveOil	<b>0.150</b>	0.125	0.141	0.121
DiatomSizeR	<b>0.330</b>	0.174	0.186	0.173
ECG5Days	<b>0.996</b>	<b>0.996</b>	0.995	0.995
FacesUCR	<b>0.939</b>	0.825	0.878	0.847
ItalyPowerD	0.831	<b>0.892</b>	0.023	0.851
MedicalImages	<b>0.946</b>	0.906	0.935	0.928
MoteStrain	0.971	<b>0.987</b>	0.970	0.979
SonyAIBOII	0.978	<b>0.989</b>	0.969	0.985
SonyAIBO	0.939	<b>0.98</b>	0.924	0.967
Symbols	<b>0.885</b>	0.822	0.724	0.761
TwoLeadECG	<b>0.825</b>	0.630	0.444	0.669
SPIRAL1	<b>0.961</b>	0.939	0.933	0.911
SPIRAL2	<b>0.966</b>	0.939	0.946	0.940
PowerCons	0.971	0.966	0.955	<b>0.977</b>
BME	<b>0.896</b>	0.800	0.858	0.666
UMD	0.885	0.855	<b>0.904</b>	0.797
DIGITS	<b>0.840</b>	0.721	0.798	0.726
LOWER	<b>0.787</b>	0.696	0.747	0.685
UPPER	<b>0.856</b>	0.678	0.787	0.687
Nb. Best	<b>22</b>	9	1	3
Avg. Rank	<b>1.56</b>	2.67	2.71	3.06

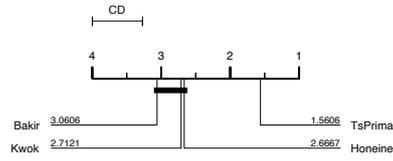


Figure 4: Nemenyi test: comparison of pre-image methods under kernel PCA reconstruction

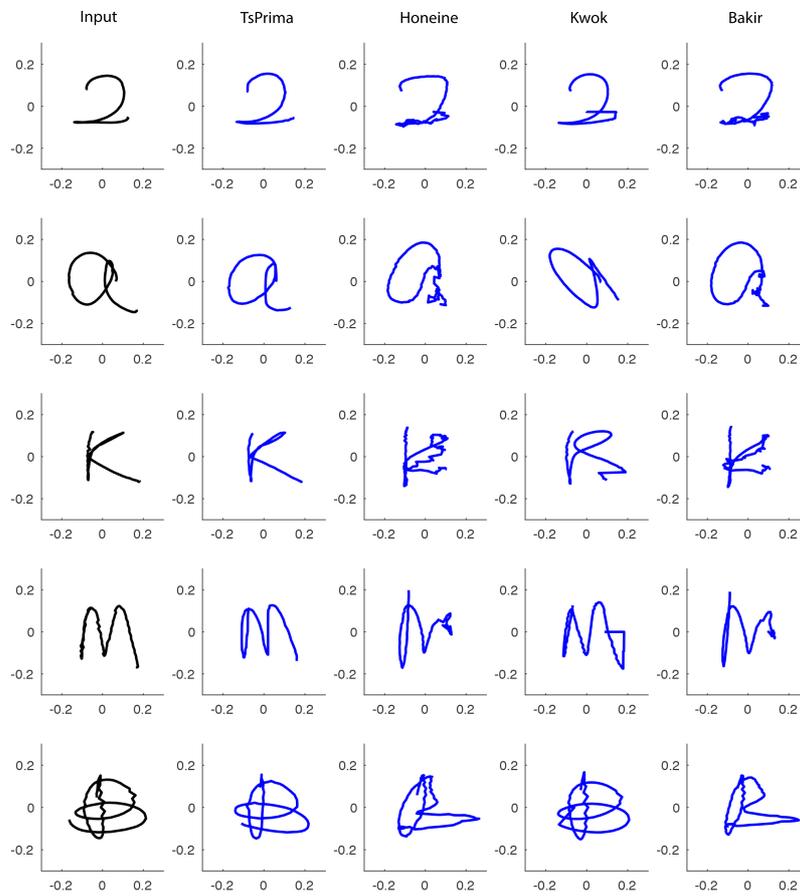


Figure 5: The time series reconstruction under kernel PCA of some samples of DIGITS, LOWER and UPPER datasets

Table 4: Quality of the denoising for several noise levels

DataSet	$\sigma^2$	TsPRIMA	Honeine	Kwok	Bakir
DIGITS	0.01	<b>0.832</b>	0.669	0.782	0.666
	0.05	<b>0.808</b>	0.619	0.742	0.627
	0.1	<b>0.791</b>	0.605	0.723	0.612
	0.15	<b>0.783</b>	0.598	0.719	0.606
LOWER	0.01	<b>0.766</b>	0.651	0.721	0.637
	0.05	<b>0.746</b>	0.614	0.689	0.606
	0.1	<b>0.736</b>	0.601	0.675	0.596
	0.15	<b>0.729</b>	0.594	0.670	0.591
UPPER	0.01	<b>0.837</b>	0.627	0.765	0.638
	0.05	<b>0.806</b>	0.579	0.712	0.600
	0.1	<b>0.789</b>	0.561	0.688	0.590
	0.15	<b>0.782</b>	0.554	0.679	0.586
Nb. Best		<b>12</b>	0	0	0
Avg. Rank		<b>1.00</b>	3.58	2.00	3.42

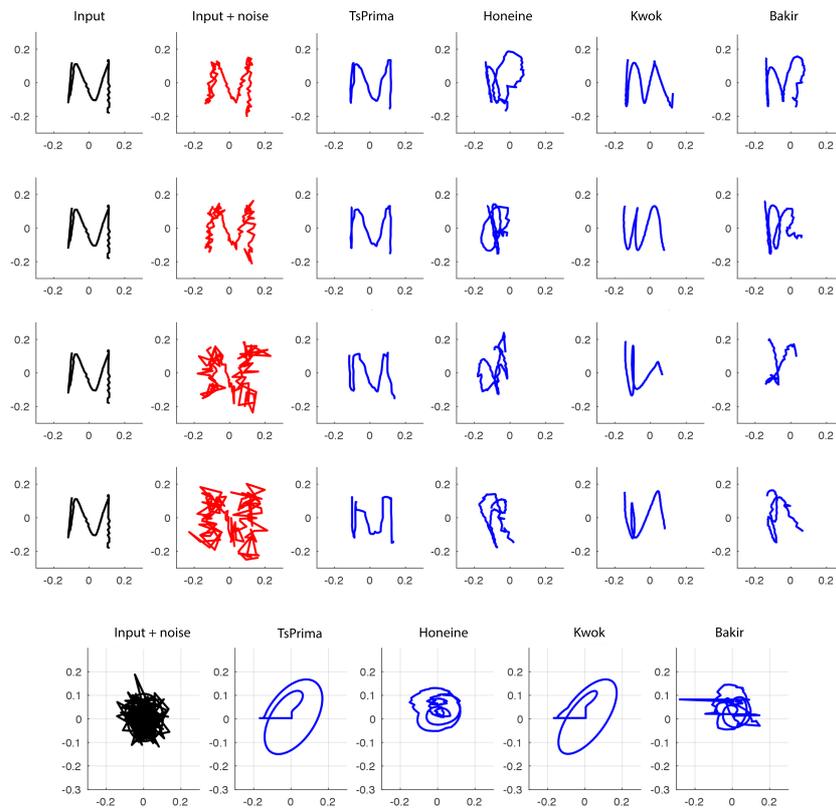


Figure 6: Time series denoising under kernel PCA of noisy samples of SPIRAL2 and of the class “M” of UPPER dataset.

446 5.3. Time series representation learning

447 For time series representation learning, the kernel  $k$ -SVD ( $\tau = 5$ ) is used  
 448 to learn, for each class of the considered datasets, the dictionary  $\Phi(X)\mathcal{B}$  and  
 449 the sparse representations  $\mathcal{A} = [\mathbf{a}_1, \dots, \mathbf{a}_N]$  of its membership time series, as  
 450 defined in Section 2.2. The pre-images  $D^*$  and  $X^*$  of the dictionary  $\Phi(X)\mathcal{B}$  and  
 451 of the sparse codes  $\mathcal{A}$  are then obtained by considering  $\gamma = \mathcal{B}$  and  $\gamma = \mathcal{B}\mathcal{A}$ ,  
 452 respectively. The quality of the learned sparse representations is then measured  
 453 as the similarity  $\text{DTAK}(\mathbf{x}_i, \mathbf{x}_i^*)$  between each time series  $\mathbf{x}_i$  and the pre-image  
 454  $\mathbf{x}_i^*$  of the sparse representation  $\Phi(X)\mathcal{B}\mathbf{a}_i$ . Table 5 gives the average quality  
 455 of the learned representations for each dataset and each pre-image estimation  
 456 method. Figure 7 gives the critical difference diagram related to the Nemenyi  
 457 test for the average ranking comparison of the studied methods. Figure 8 shows  
 458 the learned representations for some time series of DIGITS, LOWER and UPPER  
 459 datasets and Figure 9 illustrates, for a challenging sample of the class “k” of  
 460 LOWER dataset, the learned representations as well as the top 3 atoms involved  
 461 in its reconstruction.

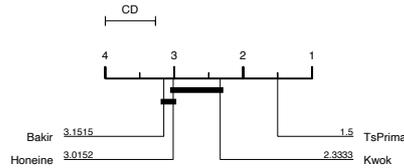


Figure 7: Nemenyi test: comparison of pre-image methods under kernel  $k$ -SVD representation learning

Table 5: Quality of the time series representation learning under Kernel  $k$ -SVD

DataSet	TSPRIMA	Honeine	Kwok	Bakir
CC	<b>0.788</b>	0.730	0.751	0.732
GunPoint	0.993	<b>0.994</b>	0.992	0.985
CBF	<b>0.917</b>	0.862	0.900	0.872
OSULeaf	<b>0.996</b>	<b>0.996</b>	0.995	<b>0.996</b>
SwedishLeaf	<b>0.789</b>	0.659	0.691	0.623
Trace	<b>0.687</b>	0.514	0.602	0.514
FaceFour	<b>0.971</b>	0.940	0.959	0.947
Lighting2	<b>0.991</b>	0.961	0.982	0.968
Lighting7	<b>0.961</b>	0.934	0.947	0.934
ECG200	0.953	<b>0.957</b>	0.950	0.941
Adiac	<b>0.184</b>	0.122	0.131	0.117
FISH	<b>0.757</b>	0.553	0.579	0.560
Beef	0.411	0.555	0.605	<b>0.621</b>
Coffee	0.596	<b>0.607</b>	0.586	0.560
OliveOil	0.145	0.133	<b>0.152</b>	0.120
DiatomSizeR	<b>0.287</b>	0.177	0.198	0.178
ECG5Days	<b>0.996</b>	<b>0.996</b>	0.995	0.994
FacesUCR	<b>0.917</b>	0.834	0.878	0.842
ItalyPowerD	<b>0.800</b>	0.781	0.034	0.728
MedicalImages	<b>0.937</b>	0.860	0.930	0.878
MoteStrain	0.969	0.970	<b>0.971</b>	0.970
SonyAIBOII	0.974	<b>0.975</b>	0.973	<b>0.975</b>
SonyAIBO	0.932	<b>0.938</b>	0.930	0.936
Symbols	<b>0.811</b>	0.785	0.794	0.755
TwoLeadECG	<b>0.810</b>	0.617	0.411	0.629
SPIRAL1	<b>0.944</b>	0.913	0.920	0.914
SPIRAL2	<b>0.964</b>	0.936	0.949	0.937
PowerCons	<b>0.968</b>	0.946	0.957	0.951
BME	<b>0.872</b>	0.734	0.843	0.622
UMD	0.888	0.842	<b>0.905</b>	0.788
DIGITS	<b>0.822</b>	0.699	0.793	0.706
LOWER	<b>0.773</b>	0.678	0.738	0.671
UPPER	<b>0.840</b>	0.664	0.797	0.675
Nb. Best	<b>24</b>	7	3	3
Avg. Rank	<b>1.5</b>	3.02	2.33	3.15

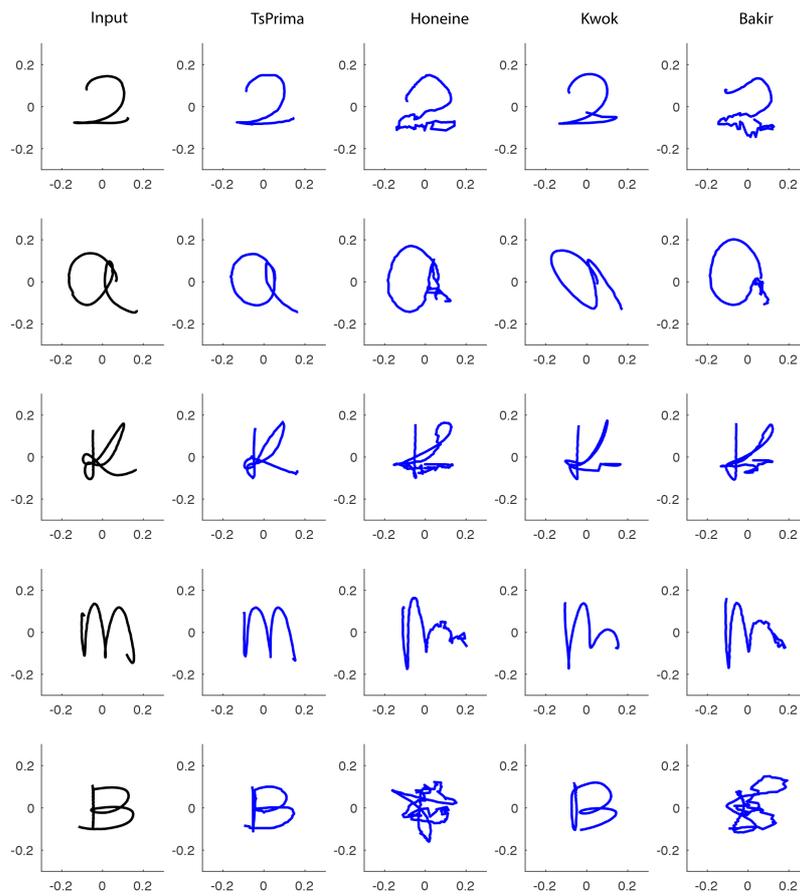


Figure 8: The learned time series representations under kernel  $k$ -SVD of some samples of DIGITS, LOWER, UPPER datasets

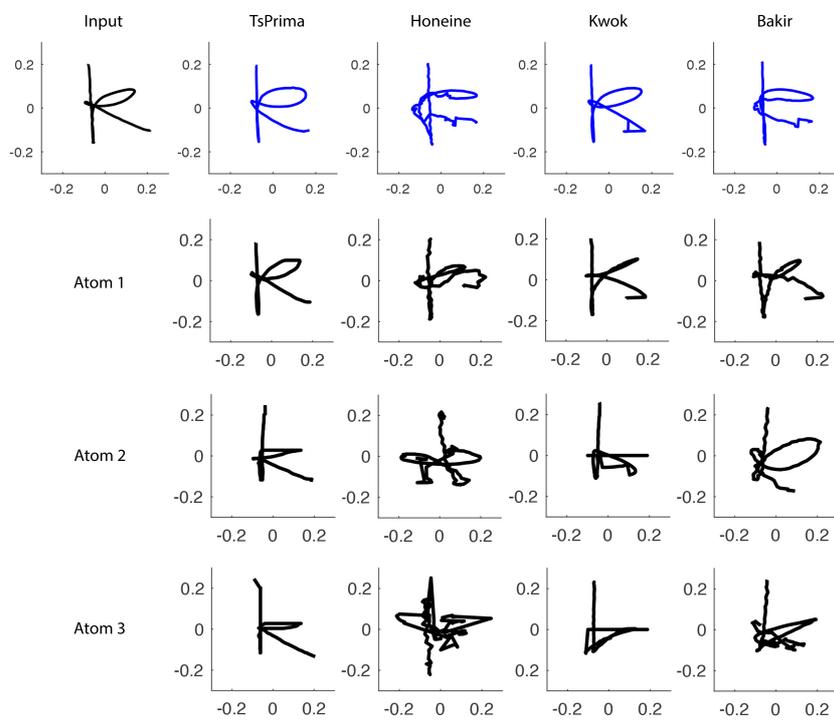


Figure 9: The sparse representation of a time series of the class “k” of LOWER dataset and the top 3 involved atoms for its reconstruction

462 5.4. Further comparison

463 In the previous experiments (Sections 5.1 to 5.3), we have evaluated the  
 464 performances of TsPRIMA that are mainly due to two major ingredients : 1)  
 465 the defined temporal embedding function  $f_r$  (Section 4.2) and 2) the proposed  
 466 transformation  $R$  to preserve an isometry between the time series embedding  
 467 space and the feature space (Section 4.1). In this last part, the aim is to evaluate  
 468 the efficiency of the proposed transformation  $R$ , regardless of the effect of  $f_r$ .  
 469 For that, TsPRIMA is compared to the alternative methods Honeine, Kwok and  
 470 Bakir once all the time series embedded into the same metric space; namely,  
 471 all the pre-image estimation methods are performed between the time series  
 472 embedding space and the feature space. Similar experiments are performed on  
 473 the 33 public datasets (Table 1), the results obtained for the three tasks are  
 474 summarised into Table 6 and the related Nemenyi tests are given in Figure 10.

Table 6: Further comparisons for pre-image estimation

		TsPRIMA	Honeine	Kwok	Bakir
Averaging	Nb. Best	<b>19</b>	<b>20</b>	4	<b>19</b>
	Avg. Rank	<b>2.23</b>	<b>2.21</b>	3.35	<b>2.21</b>
Reconstruction (kernel PCA)	Nb. Best	<b>24</b>	10	0	1
	Avg. Rank	<b>1.56</b>	2.35	3.05	3.05
Denoising (kernel PCA)	Nb. Best	<b>12</b>	0	0	0
	Avg. Rank	<b>1.50</b>	3.25	2.62	3.12
Rep. Learning (kernel $k$ SVD)	Nb. Best	<b>25</b>	8	1	2
	Avg. Rank	<b>1.44</b>	2.67	2.58	3.32

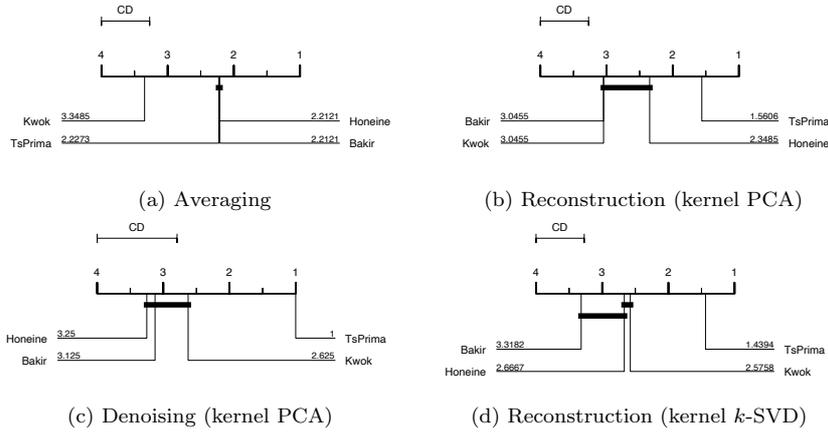


Figure 10: Nemenyi Tests.

475 *5.5. Overall analysis*

476 The experiments conducted in Sections 5.1 to 5.3 show that the proposed  
477 method TSPRIMA leads on almost all the datasets and through the three stud-  
478 ied tasks to the best results. On the other hand, the performances obtained by  
479 the alternative methods seem slightly equivalent and lower than those obtained  
480 by TSPRIMA.

481  
482 In particular, for time series averaging task, we can see in Table 2 that the  
483 centroids estimated by TSPRIMA lead to the highest within-class similarity on  
484 almost all the datasets; namely, each centroid obtained by TSPRIMA is in gen-  
485 eral the closest to the set of time series it represents. The analysis of the critical  
486 difference diagram given in Figure 2 indicates that the next best results are ob-  
487 tained respectively by Bakir, Honeine and Kwok methods. In addition, as the  
488 state of the art methods are connected by a solid bold line, their performances  
489 remain equivalent. From Figure 3, we can see that while all the methods succeed  
490 to reconstitute the centroids of some input classes (shown on the left column) as  
491 the class "6" of DIGITS and "S" of UPPER dataset, only TSPRIMA succeeds to  
492 estimate the centroids of the most challenging classes, as the "k" class of LOWER  
493 dataset and SPIRAL1.

494  
495 For time series reconstruction, Table 3 shows that TSPRIMA leads to the  
496 highest reconstruction accuracies through almost all the datasets, followed by  
497 Honeine, Bakir and Kwok methods. Figure 4 indicates that there is no signifi-  
498 cant difference between the performances of the three state of the art methods  
499 (connected by a solid bold line). These results are assessed in Figure 5 that  
500 shows, for some input time series, the quality of the reconstructions obtained  
501 by TSPRIMA and the state of the art methods.

502  
503 For the time series denoising task, we observe from Table 4 and for all the  
504 methods that the quality of the denoising decreases when the intensity of noise  
505 increases. This result is illustrated in Figure 6, that shows the denoising results  
506 of the time series "M" of UPPER dataset and of the highly noisy time series of  
507 SPIRAL2 dataset. In particular, note that that Kwok and TSPRIMA methods  
508 lead to the best results on SPIRAL2 data and seem less sensitive to noise than  
509 Honeine and Bakir methods.

510  
511 Lastly, for time series representation learning task, Table 5 indicates that  
512 each studied method leads to the best sparse representations for at least some  
513 datasets and that TSPRIMA performs better on almost all the datasets. Fig-  
514 ure 8 shows the goodness of the sparse representations obtained. While all the  
515 methods succeed to sparse represent some input time series, the time series of  
516 "k" and "B" classes appear challenging for Honeine and Bakir methods. In Fig-  
517 ure 9, we get a look on the quality of the learned atoms, that are involved into  
518 the reconstruction of the input samples. The first row gives for some input sam-  
519 ple "k" (on the left), the sparse representations learned by each method. The

520 three next rows, provide the three first atoms involved into the reconstructions.  
 521 We can see that while the first atom learned by TsPRIMA is nearly sufficient  
 522 to sparse represent the "k" input sample, the state of the art methods need  
 523 obviously more than one atom to sparse represent the input sample. Finally,  
 524 the analysis of Figure 7 indicates that Honeine method performs equivalently  
 525 than Kwok and Bakir, whereas the Kwok performances are significantly better  
 526 than those of Bakir method.

527

528 Further comparisons (Table 6) are conducted in Section 5.4 to evaluate the  
 529 efficiency of TsPRIMA related to the learned transformation  $R$ , regardless of  
 530 the temporal embedding  $f_r$ . For averaging task, TsPRIMA, Honeine and Bakir  
 531 lead equivalently to the best performances, followed by Kwok method (Figure  
 532 10 (a)). From these results we can conjecture that, linear transformations seem  
 533 sufficient to achieve good pre-image estimations for averaging task on these  
 534 datasets, as both linear and non linear approaches (TsPRIMA, Honeine, Bakir)  
 535 perform equivalently. Furthermore, while Honeine and Bakir involve the whole  
 536 datasets for the centroid pre-image estimations, Kwok uses a subset of samples  
 537 into the neighbourhood of  $\varphi$ , which may explain the slightly lower performances  
 538 of Kwok method. Note that, although TsPRIMA involves, similarly to Kwok  
 539 method, fewer samples into the neighbourhood of  $\varphi$ , it succeeds to reach the  
 540 best performances thanks to the efficiency of the learned transformation  $R$ .  
 541 For the remaining tasks reconstruction, denoising and representation learning,  
 542 TsPRIMA achieves the highest performances, followed by far by Honeine, Kwok  
 543 and Bakir (Figure 10 (b), (c) and (d)), which assesses the crucial contribution  
 544 of the learned transformations  $R$  of TsPRIMA. Lastly, of particular note is that  
 545 Honeine and Bakir that involve the whole training samples induce much com-  
 546 putations, specifically for the time series embedding process, than Kwok and  
 547 TsPRIMA that require fewer samples into the neighbourhood of  $\varphi$ .

548

549 Finally, as all the studied methods propose closed-form solutions, they lead  
 550 to comparable complexities. However, for large data, TsPRIMA and Kwok meth-  
 551 ods are expected to perform faster as requiring fewer samples on the neighbor-  
 552 hood of  $\varphi$  than Honeine and Bakir that involve the whole samples for pre-image  
 553 estimation. Note that the complexity of the proposed solutions is mainly re-  
 554 lated to the matrix inversion operator. In Kwok method, the inversion of  $ZZ^T$   
 555 required in Eq. (21), with  $Z$  of dimension  $(q \times n)$  and  $n$  is the neighbourhood  
 556 size, induces a complexity of  $O(q^2n) + O(q^3)$ ; as  $q$  is in general small and fixed  
 557 beforehand, the overall complexity is about  $O(n)$ . For Honeine method, Eq.  
 558 (24) requires two inversions of  $XX^T$  and  $K$ , which induces, respectively, a com-  
 559 plexity of  $O(d^2N) + O(d^3)$  and  $O(N^3)$ , that leads to an overall complexity of  
 560  $O(N^3)$ . For Bakir method, Eq. (26), requires the inversion of the Gram matrix,  
 561 which leads to a complexity of  $O(N^3)$ . For TsPRIMA, Eq. (32) involves the  
 562 inversion of  $XX^T$ , with  $X$  is of dimension  $(d \times n)$ ,  $d$  is the time series length  
 563 and  $n$  is the neighbourhood size. The induced complexity is of  $O(d^2n) + O(d^3)$ .  
 564 For the time series embedding part, the complexity is mainly related to the  
 565 time warping function which is of order  $O(d^2n)$ . As  $d$  is in general higher than

566 the neighbourhood size  $n$ , the overall complexity for TSPrima is about  $O(d^3)$ .  
567 To sum up, as the neighbourhood size  $n \ll N$  and  $d \ll N$  (for not extra  
568 large time series), the complexity induced by both Kwok and TSPrima remains  
569 lower than the one of Honeine and Bakir. Note that, the Honeine method can  
570 be developed to consider only the neighbourhoods instead of all samples.

## 571 6. Conclusion

572 This work proposes TsPRIMA, a new closed-form pre-image estimation method  
573 for time series analytics under kernel machinery. The method consists of two  
574 stages. In the first step, we define a time warp embedding function, driven by  
575 distance constraints in the feature space, that allows to embed the time series in  
576 a metric space. In the second step, the time series pre-image estimation is cast  
577 as learning a linear (or a nonlinear) transformation to ensure a local isometry  
578 between the time series embedding space and the feature space. Extensive ex-  
579 periments show the efficiency and the benefits of TsPRIMA through three major  
580 tasks that require pre-image estimation: 1) time series averaging, 2) time series  
581 reconstruction and denoising and 3) time series representation and dictionary  
582 learning. Future work will focus on using pre-image estimation methods to en-  
583 hance the interpretability and the computation of deep learning tasks for time  
584 series, sequence and graph analytics.

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