



Corporate Technology, Russia

Machine Learning Methods for Environmental Monitoring and Flood Protection

UrbanFlood Workshop, 11th Nov 2010

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Outline

1. Flood monitoring
 1. Task formulation
 2. Classification of data analysis methods
 3. Flood monitoring using machine learning methods
2. Monitoring data processing
 1. Pre-processing
 2. Feature extraction
 3. Analysis
 4. Abnormal behaviour detection approach
3. Development of AI component
 1. Implementation in Java
 2. Integration into EWS
4. Further plans
 1. Effect of weather conditions
 2. Additional functionality
5. Conclusions

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Outline

1. Flood monitoring
2. Monitoring data processing
3. Development of AI component
4. Further plans
5. Conclusions

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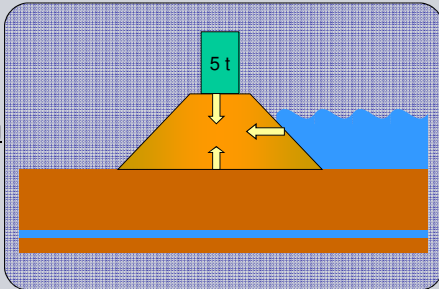
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Flood monitoring

1. Flood can be caused by:
 1. environmental conditions
 2. dike failure

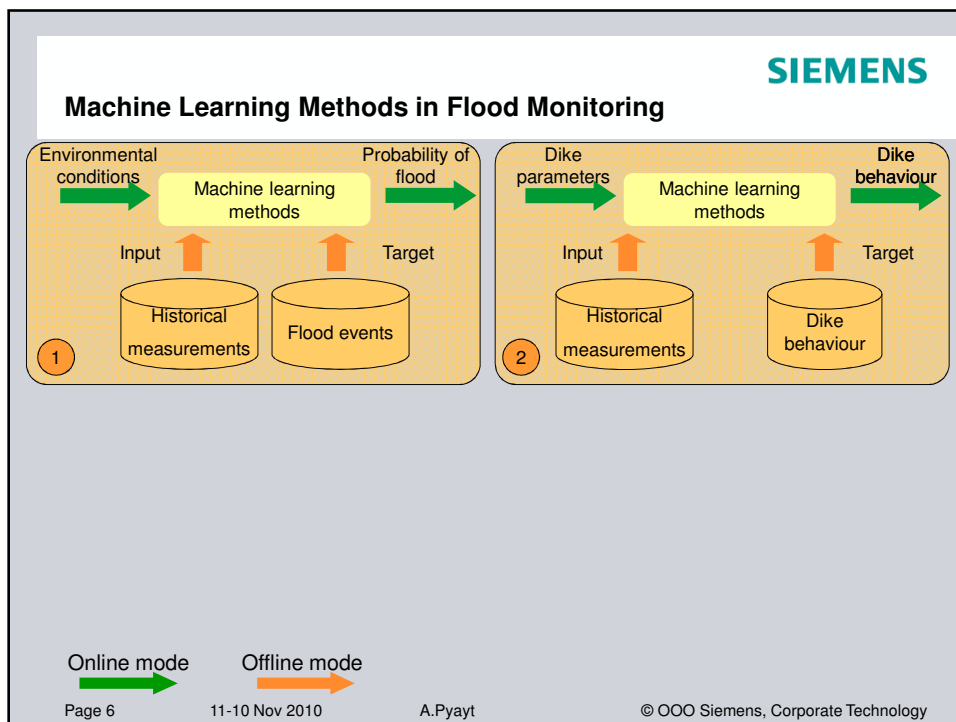
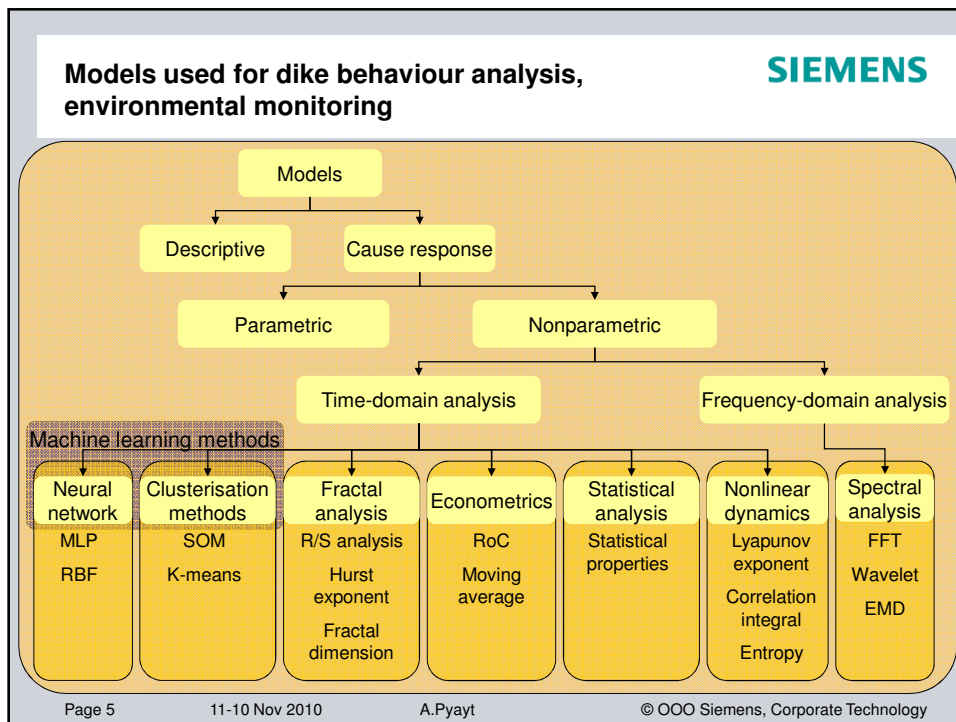
Flood monitoring = structural health monitoring + environmental monitoring

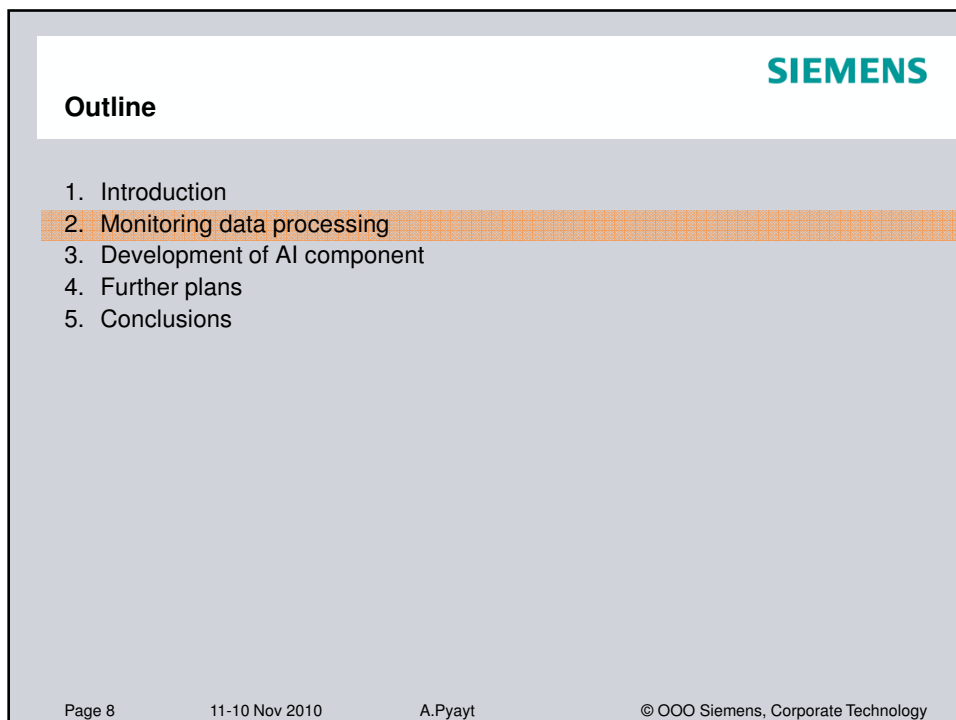
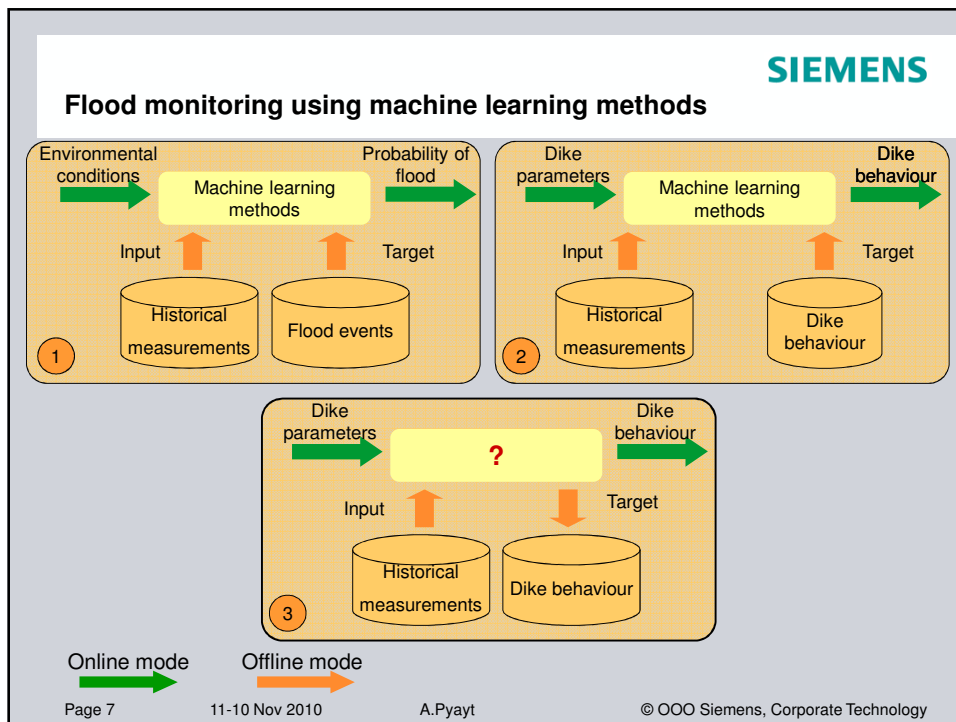
Dike abnormal behaviour detection
2. Dike failure can be caused by:
 1. environmental conditions
 2. hydrological factors
 3. human influence
3. Types of data:
 1. input (dike parameters, external parameters)
 2. output (flood probability, dike behaviour)



The diagram illustrates a cross-section of a dike. On the left, a green rectangular block labeled '5 t' represents a load on top of the dike. A downward arrow points from this load to the dike's surface. On the right, blue wavy lines represent water. A horizontal arrow points from the water towards the dike. Below the dike is a brown foundation layer with a blue horizontal line inside it, representing a water table or groundwater level.

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Schema of data processing

Base stages of data analysis

- 1 Data pre-processing
- 2 Feature extraction
- 3 Data analysis

Scenarios of data processing

The diagram shows five scenarios of data processing, each with an 'Input data flow' arrow pointing to a set of boxes representing stages 1, 2, and 3. Scenario 1: All three stages (1, 2, 3) are present, with arrows between 1-2 and 2-3, and a feedback arrow from 3 back to 1. Scenario 2: All three stages (1, 2, 3) are present, with arrows between 1-2 and 2-3. Scenario 3: Stages 1 and 3 are present, with an arrow between 1 and 3. Scenario 4: Stages 2 and 3 are present, with an arrow between 2 and 3. Scenario 5: Only stage 3 is present.

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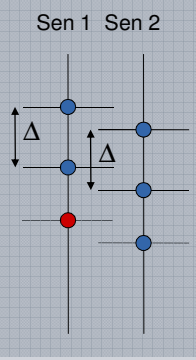
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Data pre-processing



Sen 1 Sen 2

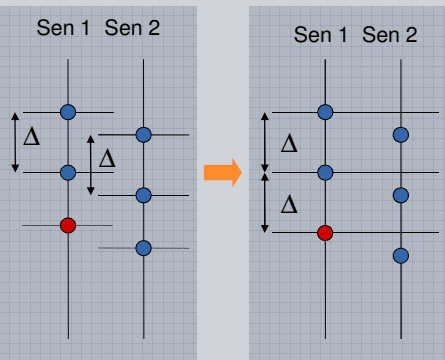
Raw data

- Measurement
- Gap

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Data pre-processing

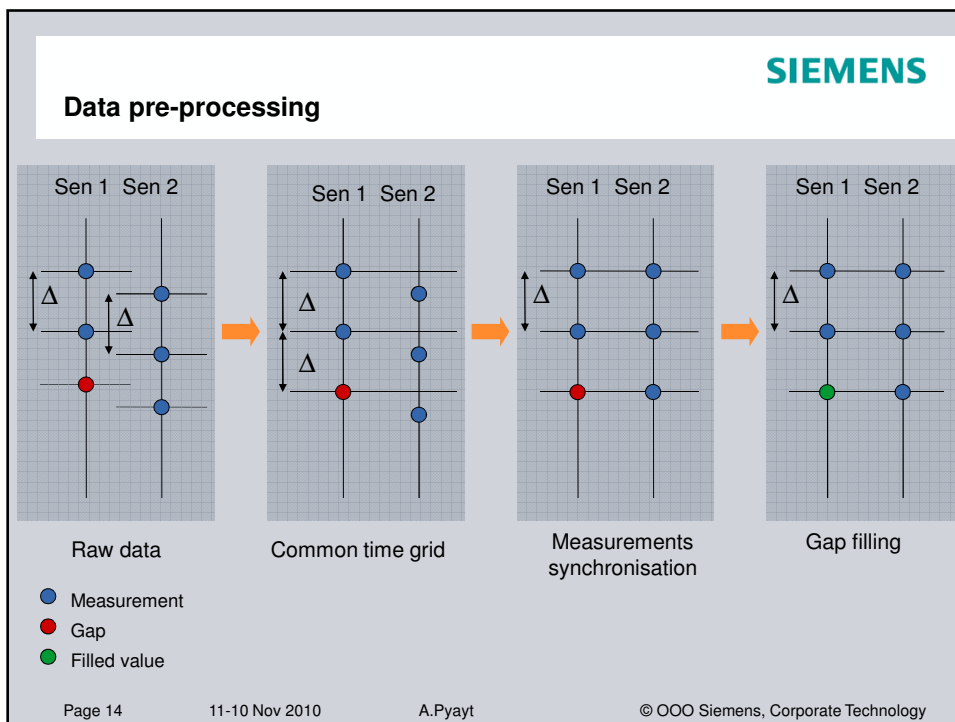
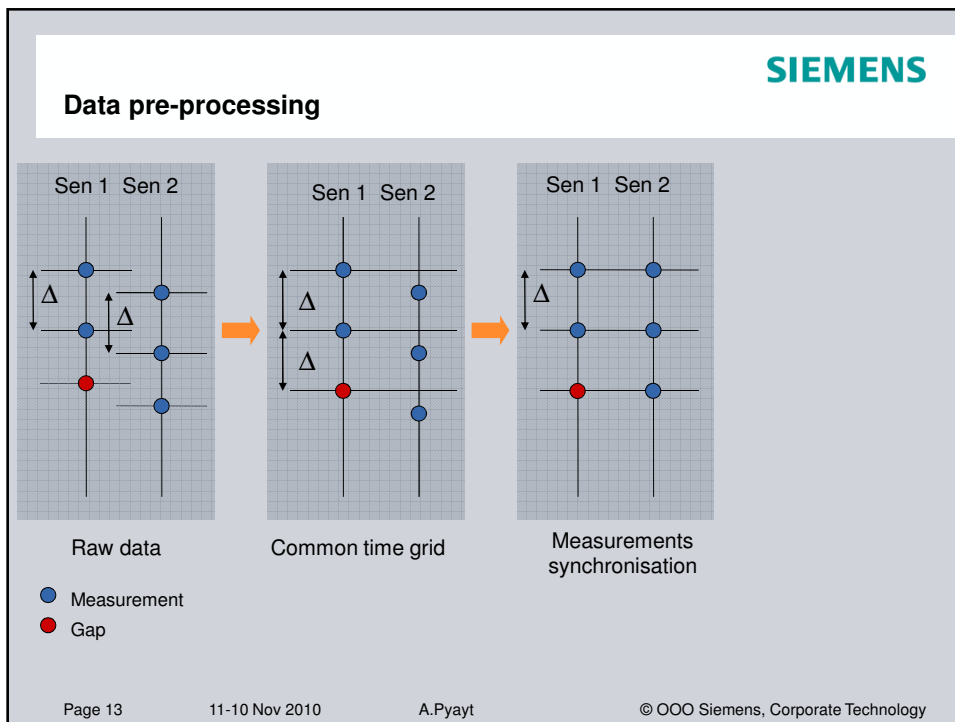


Sen 1 Sen 2 Sen 1 Sen 2

Raw data Common time grid

- Measurement
- Gap

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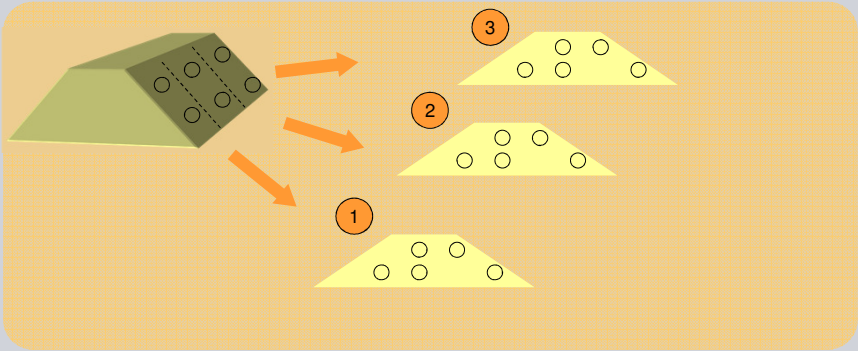
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Feature extraction Logical groups



The diagram shows a 3D terrain model on the left with several circular markers on its surface. Three orange arrows point from this model to three separate 2D trapezoidal regions on the right, labeled 1, 2, and 3. Each region contains a subset of the circular markers from the original model, representing the extraction of logical groups of features.

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Feature extraction
Logical groups. Physical redundancy

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The diagram illustrates the process of feature extraction from a 3D terrain model. On the left, a green 3D terrain model is shown with several circular sensor locations marked on its surface. Three orange arrows point from this model to three horizontal yellow layers, labeled 1, 2, and 3 from bottom to top. Each layer contains a set of white circles representing sensor locations. A red oval highlights a specific sensor location on the top layer (3), with a label 'Placement' pointing to it.

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Feature extraction
Logical groups. Physical redundancy


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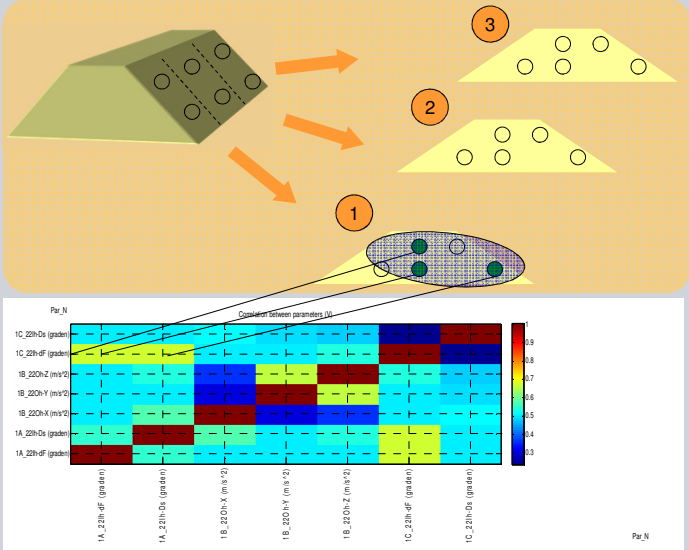
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Feature extraction

Logical groups. Analytical redundancy






The diagram illustrates the process of feature extraction from a 3D grid. It shows three logical groups (1, 2, 3) extracted from the grid. Below this, a heatmap shows the correlation between parameters. The parameters listed are:

| Par_N | 1A_22h-df (gsden) | 1A_22h-Da (gsden) | 1B_22Ch-Y (m/s²) | 1B_22Ch-X (m/s²) | 1B_22Ch-Z (m/s²) | 1C_22h-df (gsden) | 1C_22h-Da (gsden) |
|-------------------|-------------------|-------------------|------------------|------------------|------------------|-------------------|-------------------|
| 1C_22h-Da (gsden) | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 |
| 1C_22h-df (gsden) | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 |
| 1B_22Ch-Z (m/s²) | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 |
| 1B_22Ch-Y (m/s²) | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 |
| 1B_22Ch-X (m/s²) | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 |
| 1A_22h-Da (gsden) | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 |
| 1A_22h-df (gsden) | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 | 0.95 |

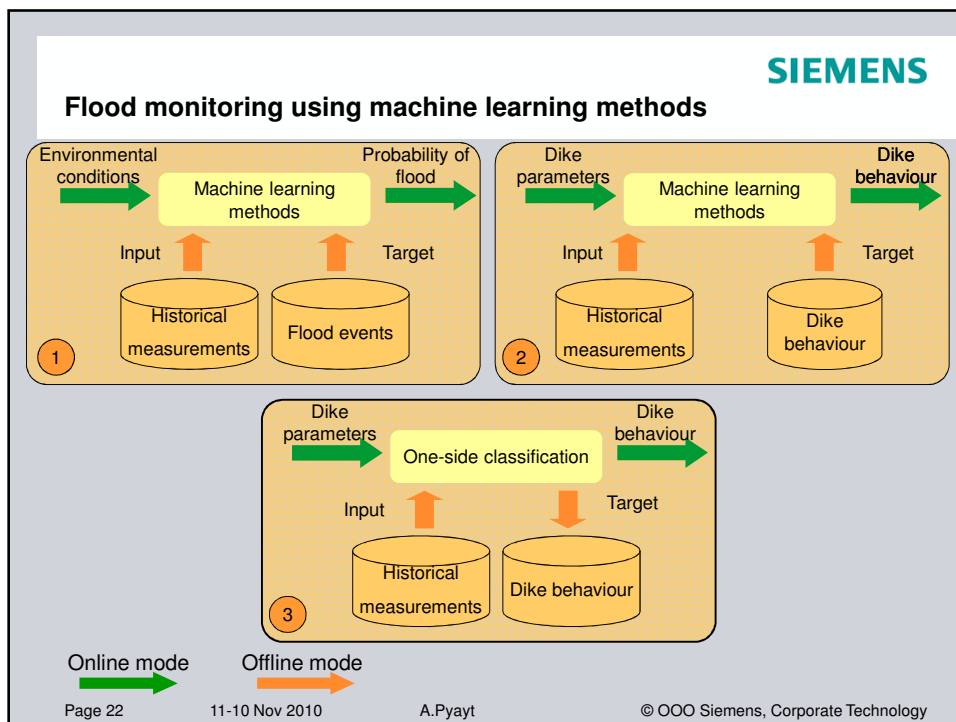
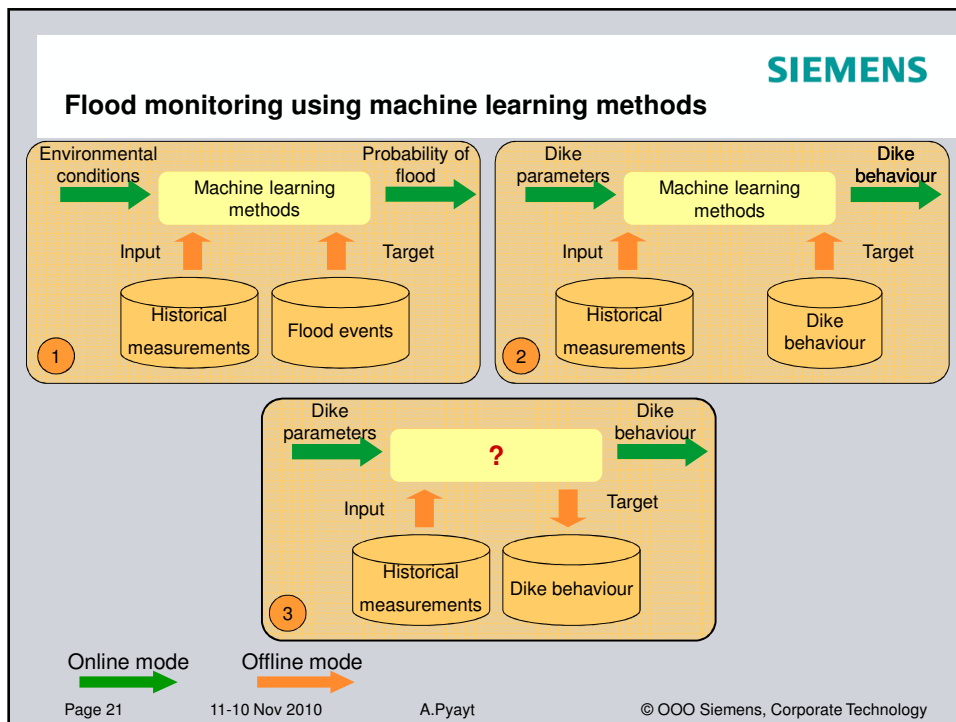
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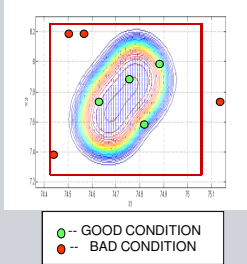


Data analysis
One-side classification**SIEMENS**

The advantages of the neural clouds concept in comparison with cube:

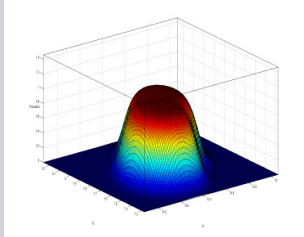
- *More sensitive to the changes in the system than box approach*
- *Allows to extract non linear dependencies between sensors*
- *Early detection of incompatibilities among sensors*

2 D data



● -- GOOD CONDITION
● -- BAD CONDITION

Neural Cloud for raw data

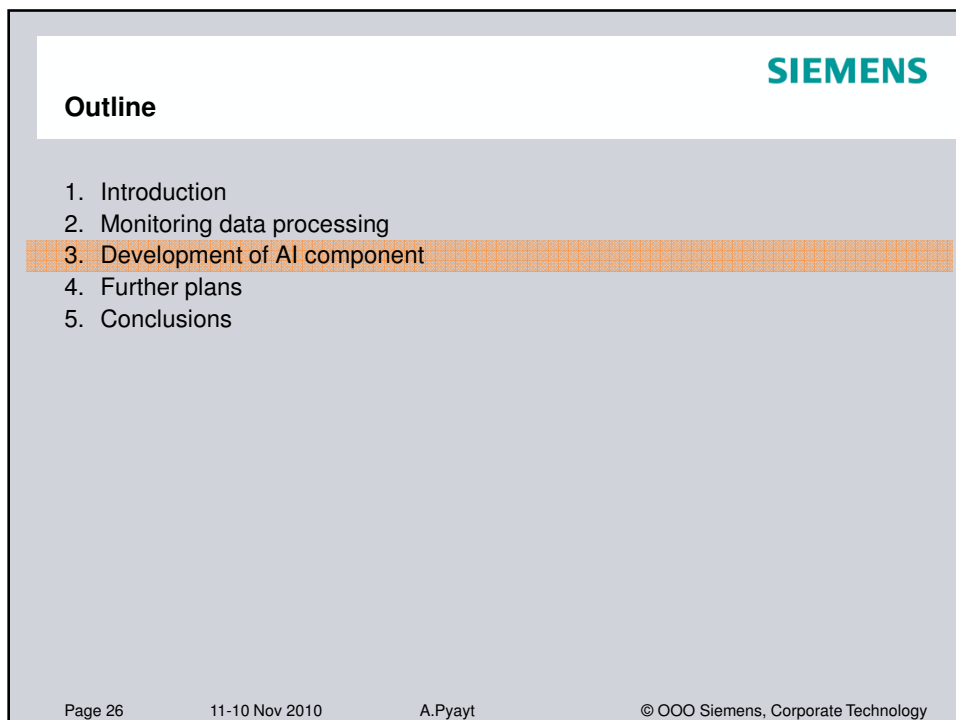
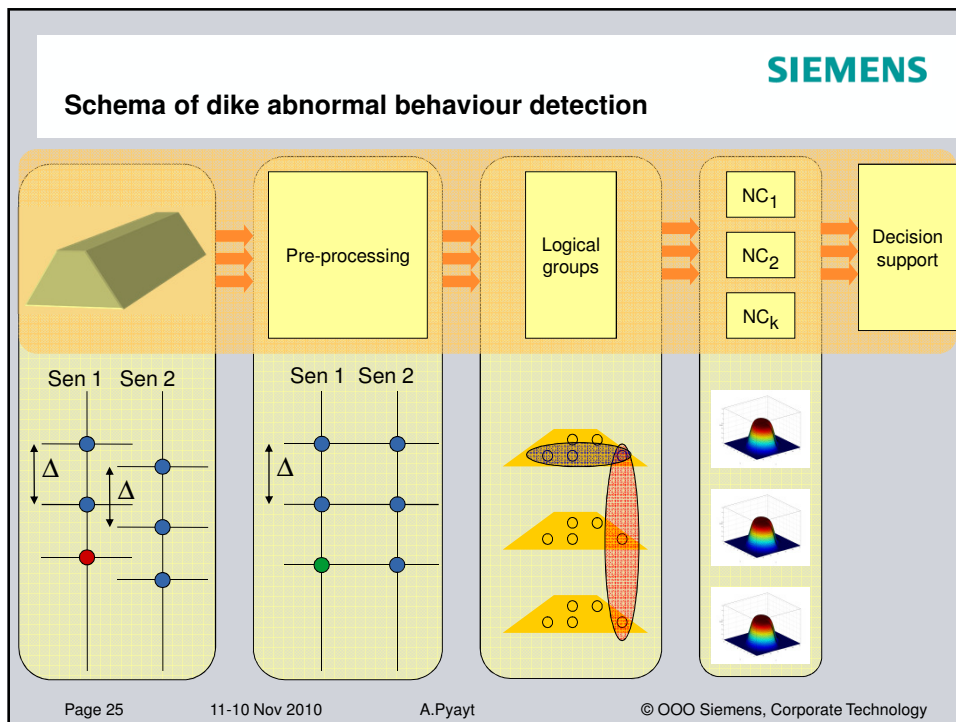


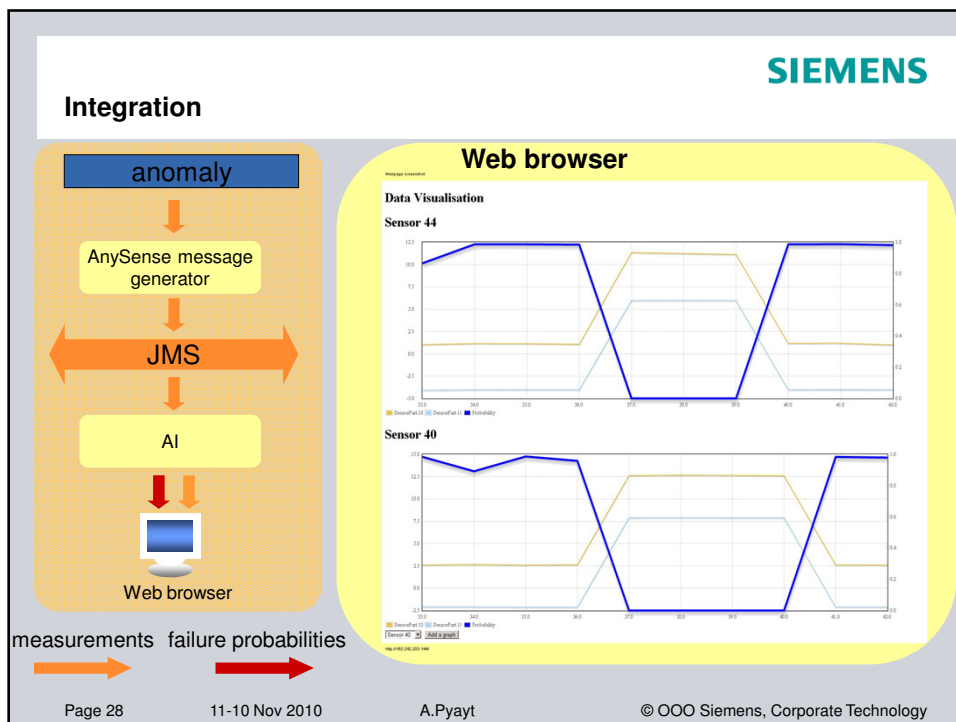
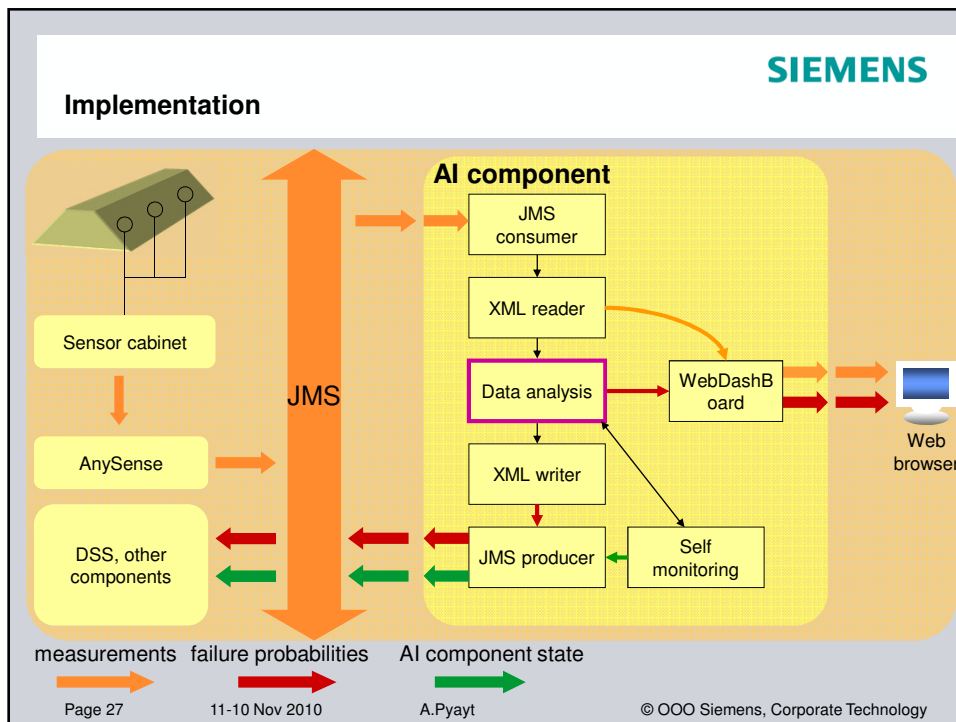
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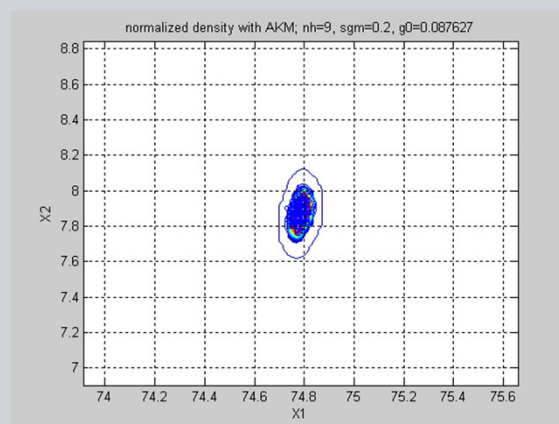


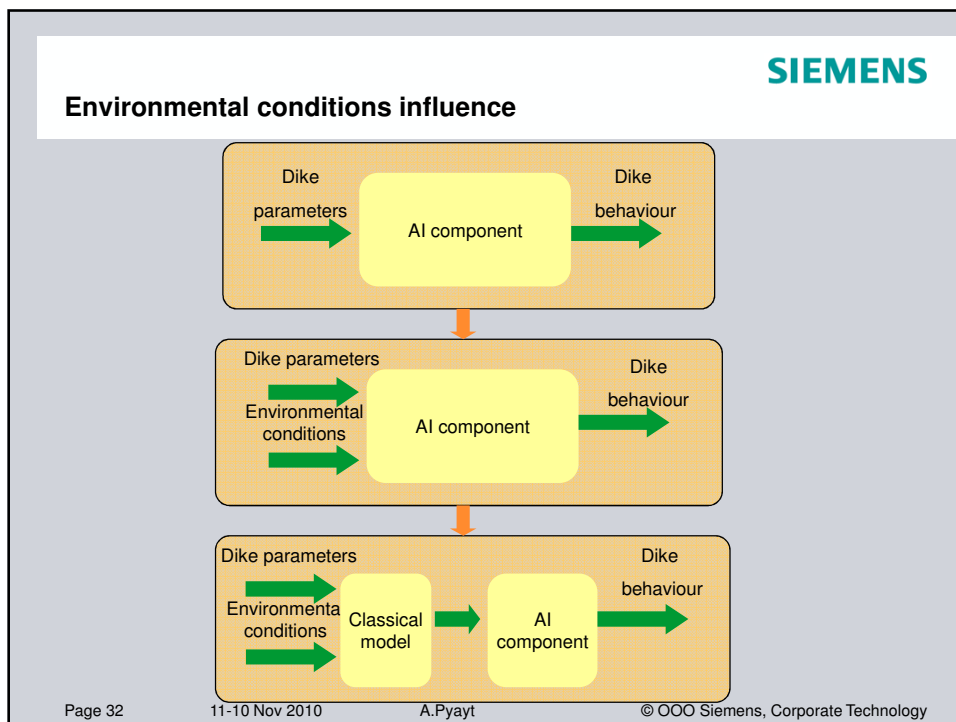
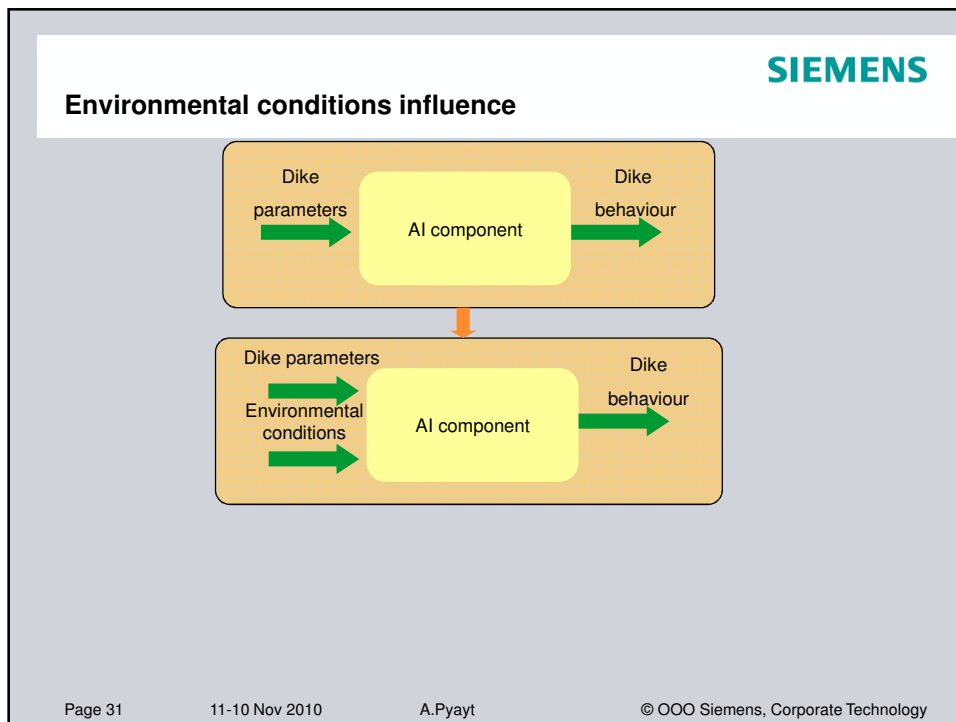


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Example of cluster movement





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Conclusions

Summary

- Appropriate machine learning method for one-side classifiers selected
- Data processing cascade defined
- Possible combination of data processing stages reviewed
- AI component integrated into Early Warning System (EWS) prototype
- First tests completed on real-time, real-world data

Outlook

- Adaptation to environmental conditions and seasonal changes
- Development of hybrid system identification: physical models extended by machine learning methods
- Automated configuration of AI component for any dike

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