FONDAZIONE links PASSION FOR INNOVATION

Deep Learning for real-time neural decoding of grasp

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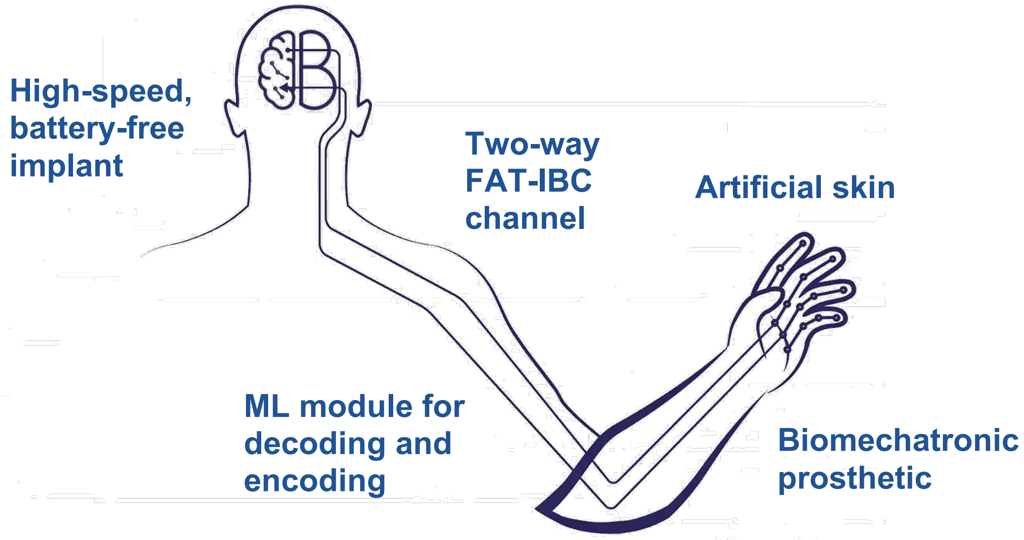
Background – B-Cratos project

Applied Data Science: focus on application → context of research in a larger project



March 2021 – February 2025
FET-OPEN 4.7M EU funding
Partners from 5 countries
Coordinated by University of Uppsala

The goal is to develop a closed-loop BCI and to validate it with NHPs (Non-Human Primates), with the following technical objectives:

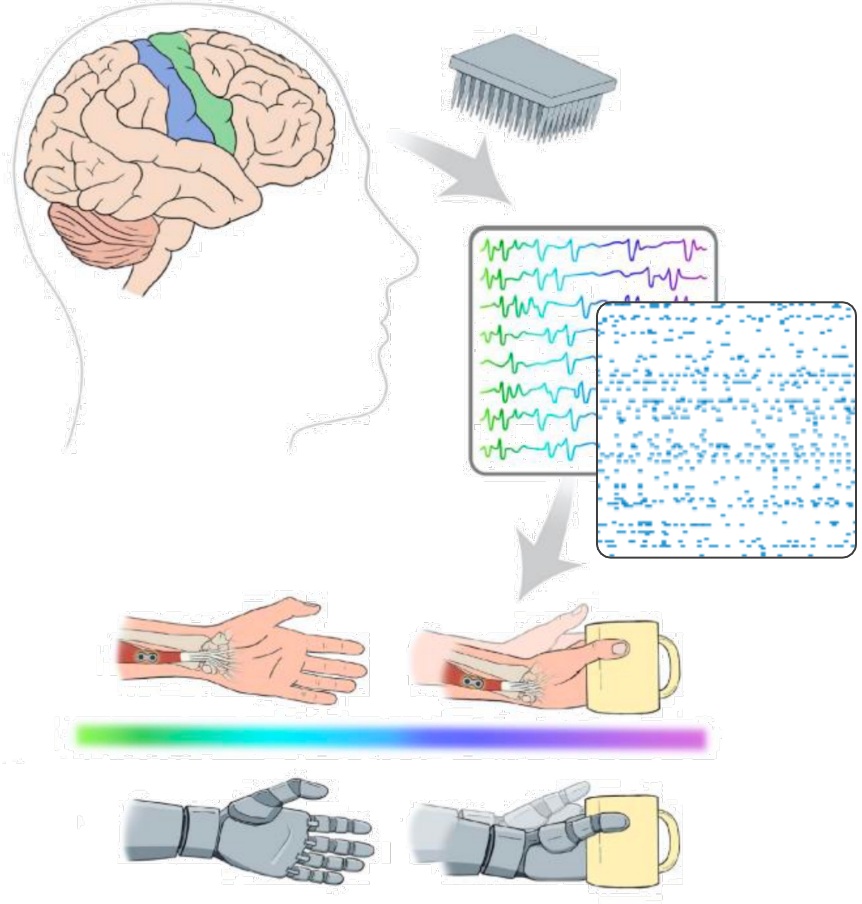
1. Proof-of-concept, high-speed, wireless brain implant capable of two-way communication without battery
2. General-purpose, high-speed intra-body communications technology (Fat-IBC)
3. **HPC based ML models deployed on embedded board for low-power inference and control**
4. Improvements of biomechatronic hand prothesis
5. High-resolution sensorized skin

This project has received funding from the European Horizon 2020 research and innovation programme under GA No 965044

Neural Decoding for Neuroprosthetics

Overview

- **Goal: translate the signal from brain implants into commands for a prothesis**
- Main steps
  - Brain electrodes pick up analogue signals from large neuron populations
  - Post-processing is applied to convert the signal to “spike-trains”: multi-channel time series of binary data
  - Decoding algorithm is applied to convert the signal to command for the prothesis



From C. Pandarinath and S. J. Bensmaia, “The science and engineering behind sensitized brain-controlled bionic hands,” Physiological Reviews, p. physrev.00034.2020, Sep. 2021 doi: 10.1152/physrev.00034.2020. **Edited.**

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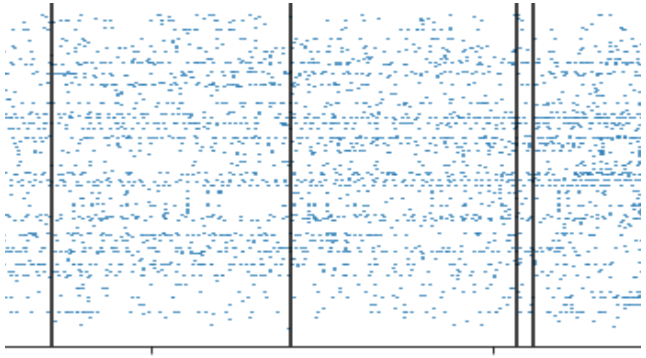
Neural Decoding

State of the art

Neural signal



Decoder

Intended outcome

- Off-line decoding is well understood, **real-time decoding is challenging**
- State-of-the-art models are simple (e.g., linear models): **Patient “learns to drive” the model**
  - Also reflects neuroscientist’s need for explainability
- Neural signal changes over time and requires daily re-training of models
- B-Cratos aims to **improve the overall accuracy of models and to re-use information across sessions**
  - Lower effort for patient, easier adoption, more natural usage
  - **Modern machine learning techniques can support this goal**

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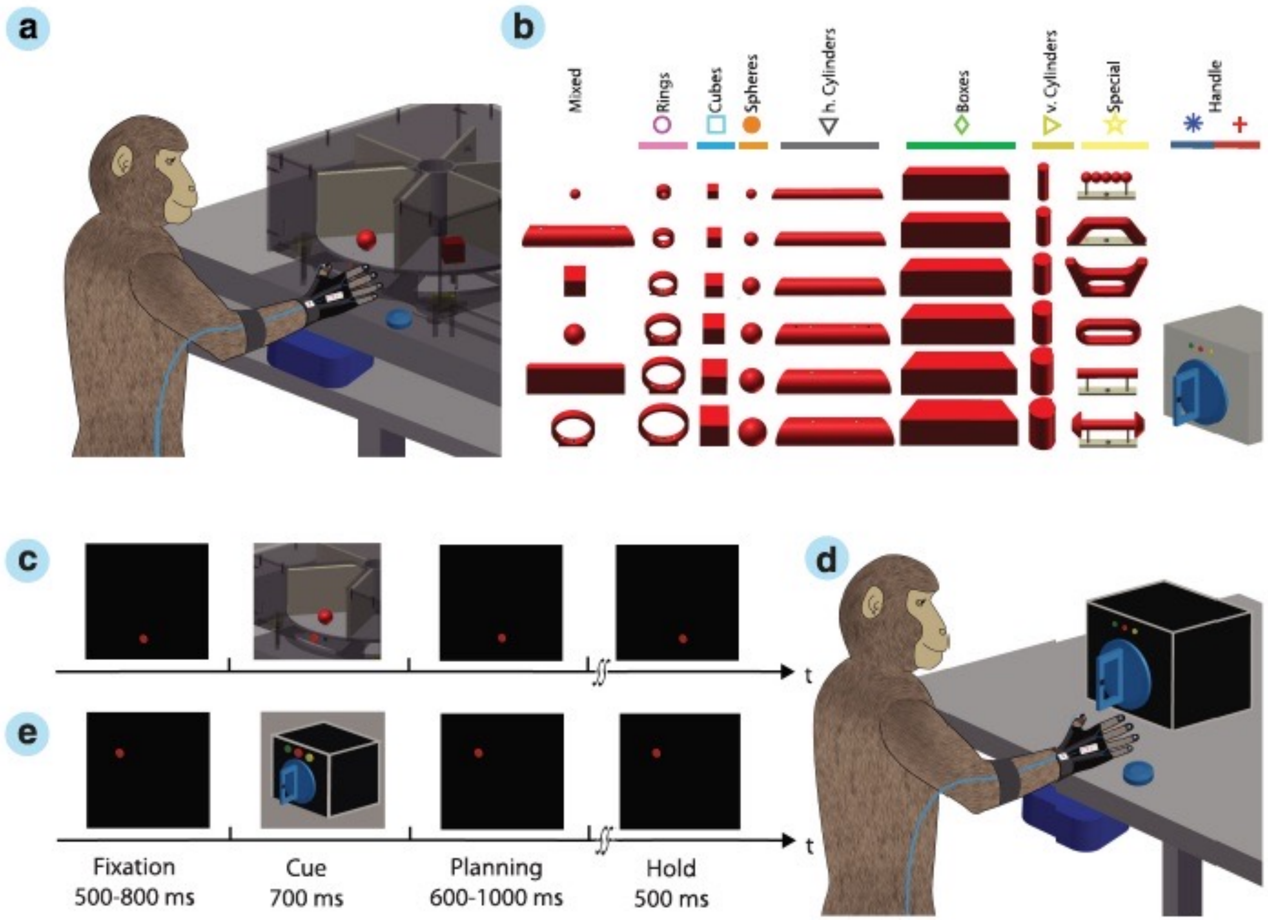
ML task overview

Working on a reference dataset

- Focused on a reference dataset provided by a partner (German Primate Center)
- Monkey trained for a grasping task
- Neural recording from multiple cortex regions
- Monkey grasping objects presented in sequence
- Objects grouped by shape and size, presented randomly
- 2 monkeys, 6 recording sessions (i.e., different days)
- **Learning Tasks**
    - Grasping phase detection
    - Object classification



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Dataset structure

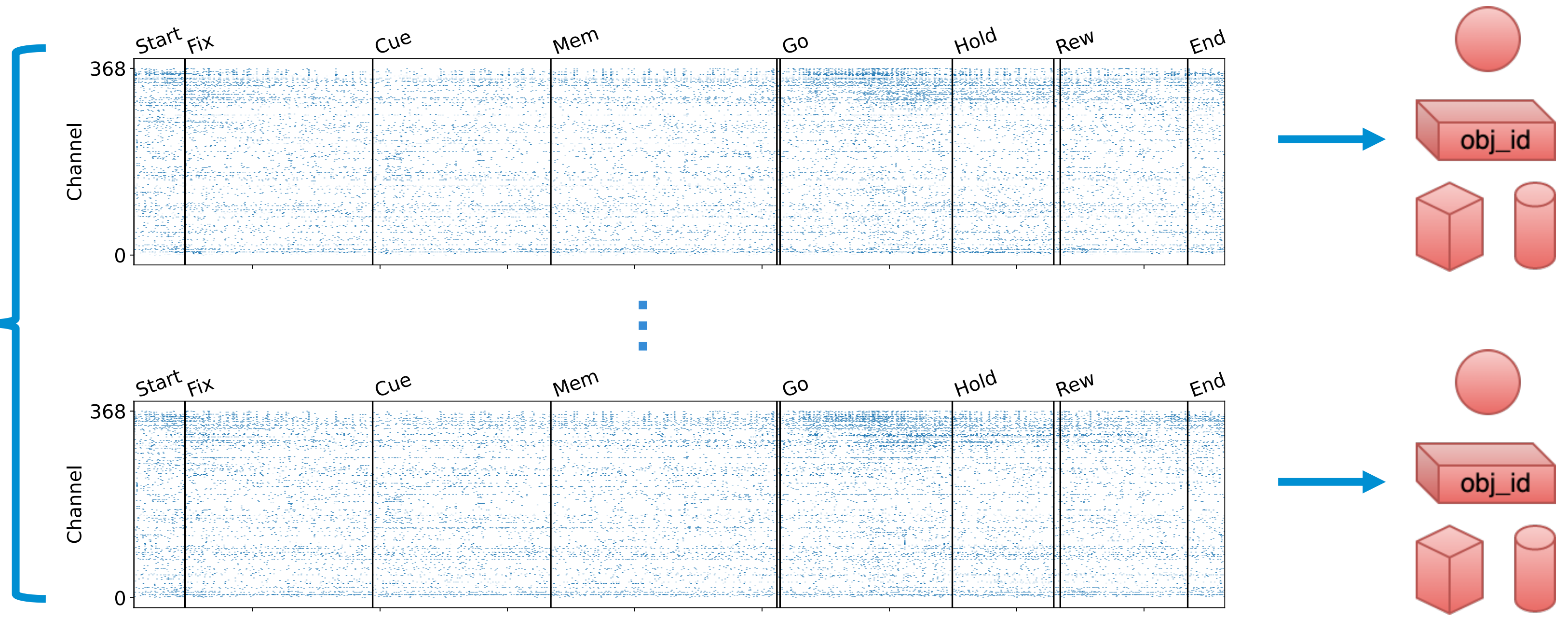
Recording sessions, trials, metadata

NHP identifier	Dataset identifier	# Channels	# Trials
M	MRec40	552	745
	MRec41	568	757
	MRec42	554	653
Z	ZRec32	391	687
	ZRec35	388	724
	ZRec50	369	610

Recording sessions

...

Trials



50 objects

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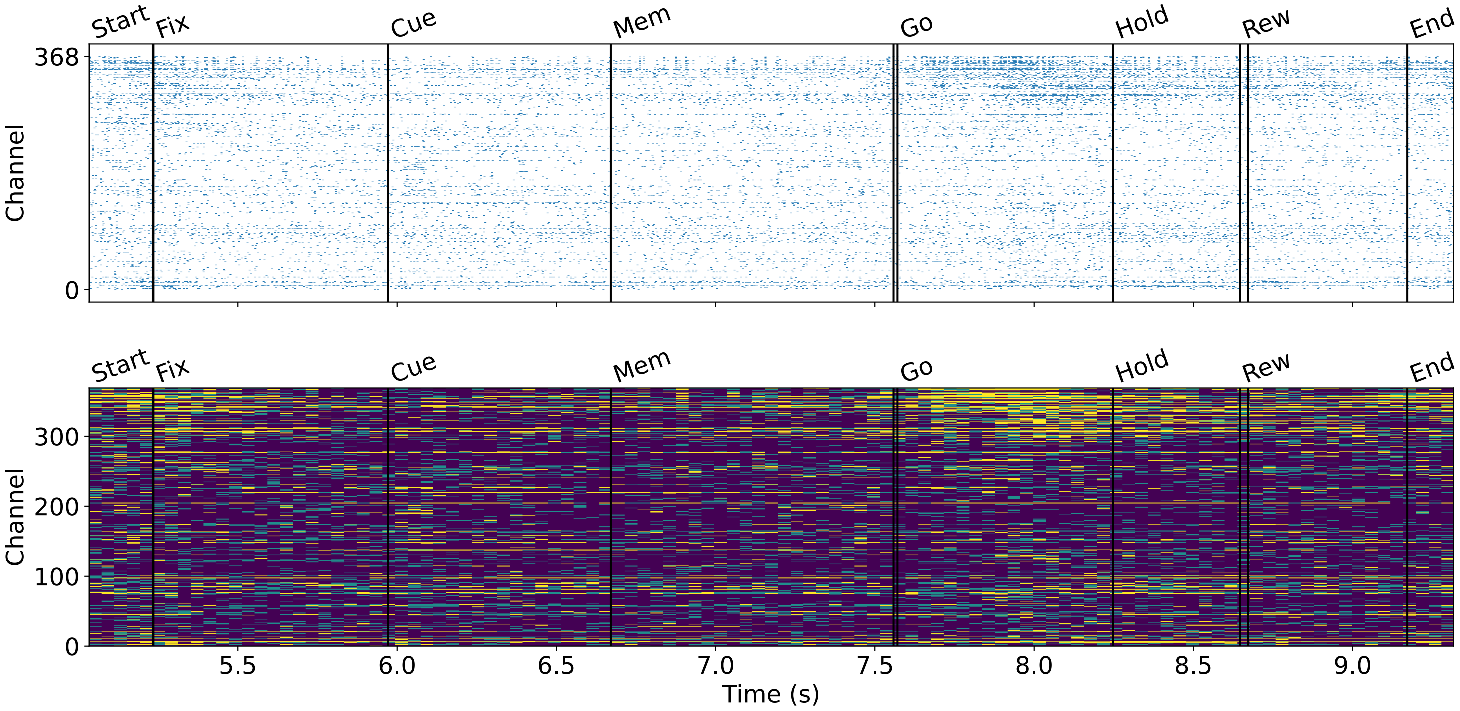
Pre-processing

Time-discretization

- Each trial discretised in bins of 40ms
- Results in dense matrix
  - *channels x time_bins*
  - *Each bin contains the number of spikes*
- Time stamps associated to a bin
- Each matrix is Associated to object id



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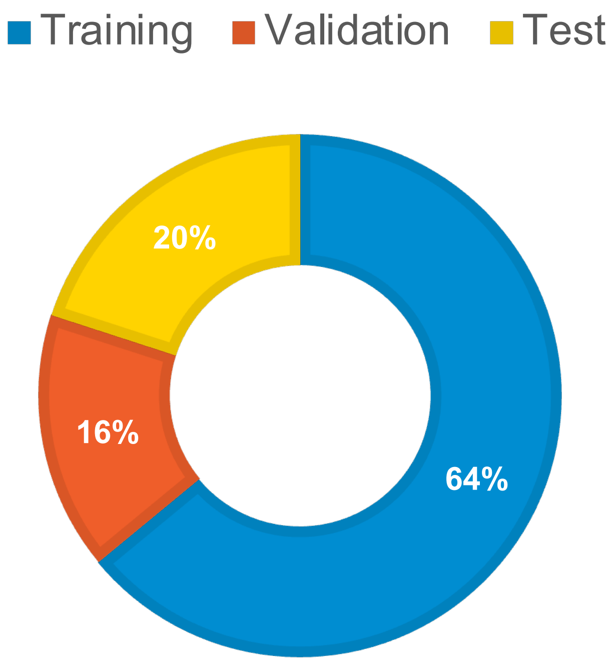
Pre-processing

Dataset split



1. Classes are de-duplicated (i.e., same object in different groups)
2. Dataset is split by trial
    1. 80% training + validation, 20% test)
    2. stratified by class
3. Split is stratified by class
4. Under-represented class are removed (i.e., less than 3 trials per session)
5. Total of 39 classes left

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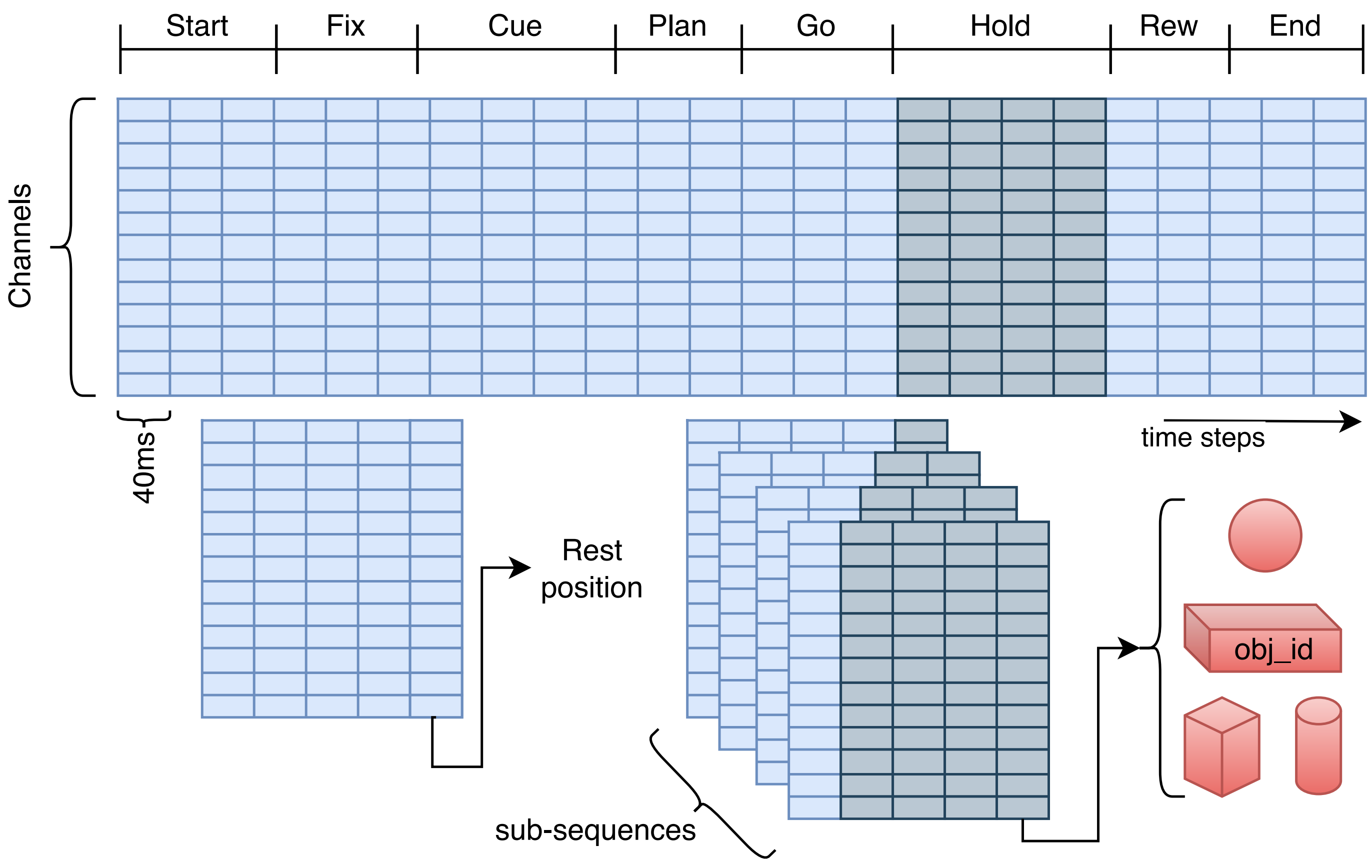
Pre-processing

Sequence extraction

Goal: simulate real-time decoding

1. Sliding windows extract sub-sequnces of 12 bins
2. Grasp phase classification includes all data labelled with 0 (no grasp) and 1 (grasp)
3. Object classification includes only the sub-sequences in the grasp phase, labelled with object ID



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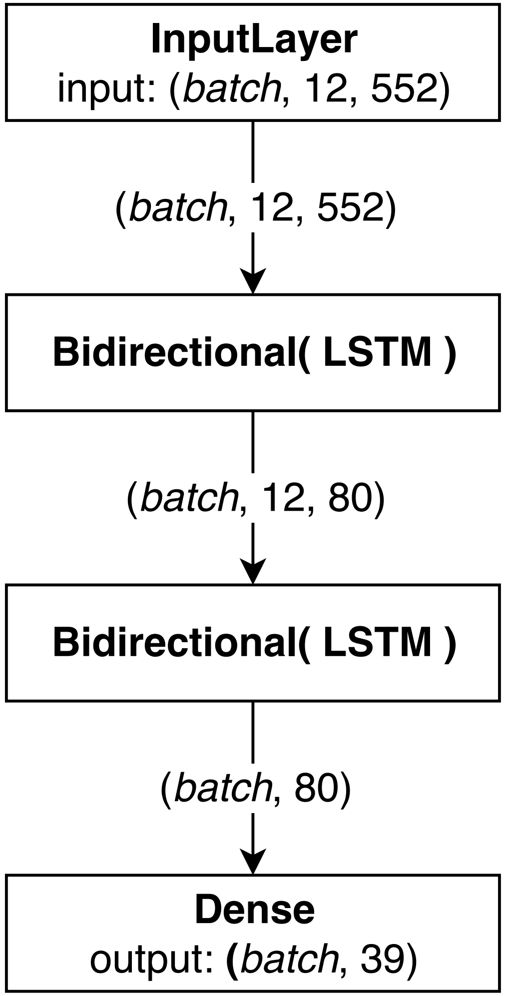
Decoding approach

Model selection

- LSTMs demonstrated good performance in literature
- Started from there (quite naïve in fact)
- **Bidirectionality** proved to be very effective
- Lots of **dropout** to prevent heavy overfitting
- Hyperparameter optimization

Hyperparameter	Values (L1=0.01, L2=0.01)	Selected M	Selected Z
LSTM layers	{ 1, 2, 3, 4 }	2	1
Hidden units	{ 16, 32, 40, 64 }	40	40
Dropout	{ 0, 0.2, 0.4, 0.6, 0.7, 0.8 }	0.8	0.7
Kernel regularisation	{ None, L1, L2, L1 + L2 }	L2	L2
Recurrent regularization	{ None, L1, L2, L1 + L2 }	L2	L1+L2
Initial learning rate	{ 10^{-3}, $2 \cdot 10^{-4}$, 10^{-4} }	10^{-3}	10^{-3}



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Results

Grasping phase detection

- Significant class imbalance here, with no grasp class ~10 times more represented than grasp class
- LSTM model reaches an accuracy of at least 98% for all datasets, the F1 score is always greater than 0.95
- Result relevant for a finite-state prosthesis control scenario
  - Each 40ms time step: predict prosthesis status (grasp vs. no-grasp)
  - 1% of unwanted movement for each time step
  - 0.1% of unresponsive prosthesis

(a) Confusion matrix for grasping phase detection (MRec40).

True	Predicted rest	Predicted grasp
rest	12824	173
grasp	25	1347

Unwanted Movement ~1%

Unresponsive prosthesis ~0.1%

(b) Grasping phase detection accuracy metrics.

Dataset id	Accuracy	F1 score
MRec40	99%	0.96
MRec41	99%	0.96
MRec42	99%	0.97
ZRec32	99%	0.96
ZRec35	98%	0.96
ZRec50	98%	0.95

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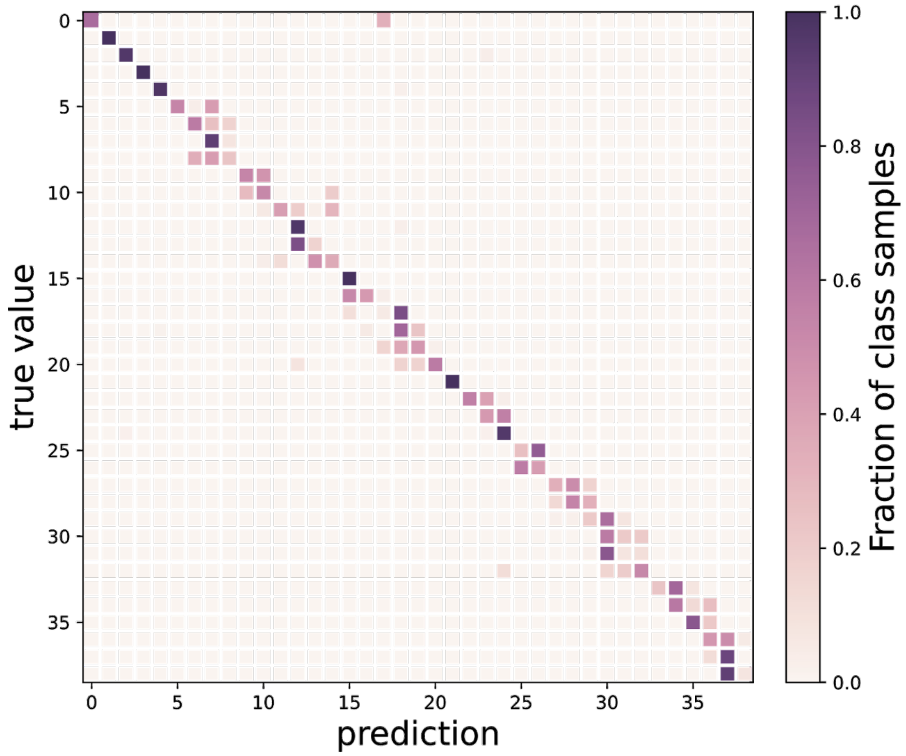
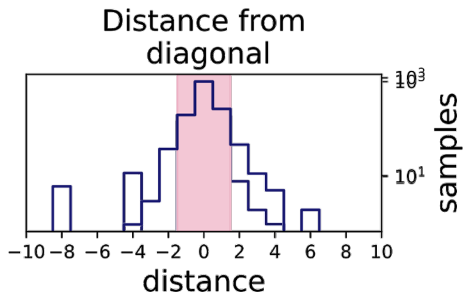
Results

Object classification

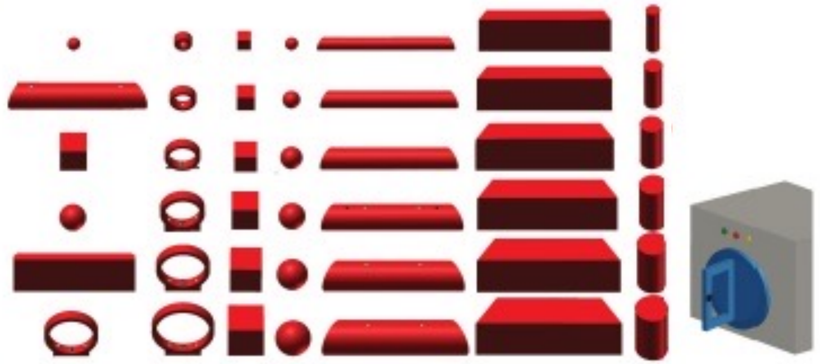




Accuracy: 61.0%

Diagonal ±1: 90.5%

- Top 1% accuracy ranging from 61% to 74% across different sessions
- Neighbouring classes referred to similar objects
  - Relaxed accuracy defined as misclassification by 1 class (i.e., distance 1 from diagonal)



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Results

Object classification – comparison with state of the art

Animal	Metric	Present work	Schaffelhofer, 2015	Fabiani, 2021
M	Accuracy	$69.7 \pm 4\%$	$62.9 \pm 3.6\%$	n/a
Z	Accuracy	$62.3 \pm 1.2\%$	$61.4 \pm 4.1\%$	n/a
Global	Accuracy Relaxed accuracy	$65.9 \pm 4.9\%$ $94.4 \pm 3.1\%$	62% 86.5%	22% 59%

- Schaffelhofer et al. report an average accuracy for the hold phase of 62% over a total of 10 recording sessions (against the six available for this work)
  - Offline naive bayesian classifier applied to the whole hold phase vs. sligding window
  - Validated with a leave-one-out (LOO) approach
  - Dataset fraction used for training was significantly higher
  - Significantly better (M) and slightly better (Z) accuracy results in a harder set-up. Significantly better relaxed accuracy
- Fabiani reported offline and online accuracy figures
  - This work outperforms both cases, despite the use of similar LSTM architechtures
  - Improvement likely due to bidirectional networks and stronger regularization

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Results

Robustness to reduction of training data

- Real life scenario involves frequent re-training, also during recording sessions
- Neuroscientist's requirement is to limit training to a minimum, and let the model work for most of the time
  - Even more relevant for patients
- Smaller training sets were evaluated
- The model is still outperforming the previous SotA down to 40% of training data

Training + validation set	Accuracy	Relaxed accuracy
80%	74.1%	98.3%
70%	70.1%	97.1%
60%	69%	93.7%
50%	62.8%	94%
40%	63.8%	92.8%
30%*	59.2%	87.5%
20%**	51%	81%

*validation is 30% of training set to ensure at least one representative per class
**validation is 40% of training set

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Remarks and future work

- LSTM can match and outperform previous approaches on a known dataset
  - More accurate prosthesis control can be enabled by modern architectures, at the expense of some explainability
- Results for relaxed accuracy are very promising for the final application
  - Continuous control of few degrees of freedom (regression on few variables)
  - Finite-state control of 5-6 grasp types (classification on fewer classes)

Future work

- Neural data evolves with time: robustness/adaptability of models is key to reduce patients and physicians effort
- Fine-tuning with limited data already proven effective
- Semi-supervised training with usage data is an open problem, inputs from the community are welcome!

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Thanks for your attention!

Acknowledgments

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