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Seasons in Drift: A Long-Term Thermal Imaging Dataset for Studying Concept Drift

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Abstract

1 The time dimension of datasets and long-term performance of machine learning
2 models have received little attention. With extended deployments in the wild,
3 models are bound to encounter novel scenarios and concept drift that cannot be
4 accounted for during development and training. In order for long-term patterns and
5 cycles to appear in datasets, the datasets must cover long periods of time. Since
6 this is rarely the case, it is difficult to explore how computer vision algorithms cope
7 with changes in data distribution occurring across long-term cycles such as seasons.
8 Video surveillance is an application area clearly affected by concept drift. For this
9 reason we publish the Long-term Thermal Drift (LTD) dataset. LTD consists of
10 thermal surveillance imaging from a single location across 8 months. Along with
11 thermal images we provide relevant metadata such as weather, the day/night cycle
12 and scene activity. In this paper we use the metadata for in-depth analysis of the
13 causal and correlational relationships between environmental variables and the
14 performance of selected computer vision algorithms used for anomaly and object
15 detection. Long-term performance is shown to be most correlated with temperature,
16 humidity, the day/night cycle and scene activity level. This suggests that the
17 coverage of these variables should be prioritised when building datasets for similar
18 applications. As a baseline, we propose to mitigate the impact of concept drift by
19 first detecting points in time where drift occurs. At this point we collect additional
20 data that is used to retraining the models. This improves later performance by an
21 average of 25% across all tested algorithms.

22 1 Introduction

23 Once computer vision algorithms step outside the lab and are deployed in real-life outdoor applica-
24 tions, their performance tends to drop significantly due to conditions changing over time, i.e. concept
25 drift [90, 24, 85]. Concept drift can materialize as gradual, recurring or sudden changes in the visual
26 representation of the scene. Existing datasets, in general, favour coverage of multiple locations
27 [32, 75] for short periods of time [46, 45, 83]. Such datasets are ill suited for exploring long-term
28 effects such as concept drift and algorithms developed on their basis are unlikely to show robustness
29 to long-term phenomena. Research studying concept drift [28, 55], uses synthetic datasets or datasets
30 augmented in order to introduce drift. This does not necessarily completely represent real-world
31 concept drift.

32 Our work presents a novel real-world dataset covering the 8 months from January to August. This
33 time span means that the dataset encompasses a wide range of weather conditions, human activity,
34 seasonal transitions, and recurring cycles such as weekdays, weekends, mornings and evenings.

35 Along with the thermal images, timestamped metadata has been gathered. The metadata includes
36 weather data such as temperature, humidity, precipitation, etc. as well as metrics for scene activity
37 level. We use the dataset to study concept drift by exploring contributing factors and demonstrating
38 their effects on algorithmic performance. By publishing the dataset, we seek to aid the community
39 in evaluating existing algorithms against a long-term benchmark and in the development of algorithms
40 that show greater robustness to long-term phenomena.

41 To explore the dataset, two common tasks are chosen, namely anomaly and people detection. These
42 tasks tend to suffer strong performance degradation when exposed to long-term concept drift [77].
43 Object detection in general or detecting people in particular is a fundamental task involved in
44 many use cases such as autonomous driving [86, 10, 8], tracking [6, 67, 73, 19] and re-identification
45 [40, 41, 26]. Common for many of the use cases is the application of object detection in unconstrained
46 environments and across long spans of time. Anomaly detection, where the goal is to detect unusual
47 behavioral patterns, is another task that is exposed to concept drift. These algorithms must be able to
48 distinguish irrelevant changes due to e.g. concept drift from emergencies such as burglaries or assaults
49 [75], car accidents [39], loitering and suspicious behaviour [89], indoor [27] and outdoor [15, 36, 43]
50 falls.

51 We select representative algorithms for each task and evaluate their performance across time and in
52 relation to environmental factors. As expected, all models exhibit performance degradation, as the
53 test data diverges from the training set. Temperature and humidity proves to influence the models
54 the most, followed by the change between day and night and the activity level of the scene. On the
55 other hand, variation in precipitation and wind do not influence the performance of the models. In
56 general, methods that learn from solving tasks that consider the entirety of the image are likely to be
57 less impacted by drift, compared to methods that consider small regions or individual pixels [76].
58 An example could be object detectors vs. autoencoders, where something like brightness is likely to
59 impact the autoencoder’s reconstruction significantly, but won’t effect the class or position of objects.
60 By including both autoencoders and object detectors we ensure that both ends of this spectrum are
61 covered in our analysis.

62 Finally, a baseline algorithm is presented to reduce the consequences of concept drift. This algorithm
63 provides additional training data from points in time where concept drift is detected. This baseline
64 is intended to encourage researchers to develop other methods of reducing the impact of concept
65 drift. We believe that our findings on this novel dataset generalize to other environments and use
66 cases, as well as other modalities and therefore will be an example to follow for future definition and
67 collection of datasets. This in turn will help the community getting closer to deploying long-term
68 computer vision algorithms for real-life outdoor applications. The main contributions of this paper
69 can be summarized as follows:

- 70 • The Long-term Thermal Drift (LTD) dataset - the longest-spanning systematically collected
71 thermal dataset comprised of 8 months of video data, containing both timestamp and weather
72 condition metadata;
- 73 • In-depth analysis of the correlational and causal relationships between the performance of
74 models and environmental factors;
- 75 • A baseline algorithm for reducing the effects of concept drift.

76 **2 Related Work**

77 **2.1 Concept Drift Detection**

78 As many systems need to be deployed and work stably for long periods of time and with input data
79 which can change both gradually and suddenly, the presence of drift and ways to deal with it is a
80 topic that has been widely studied. In computer vision it is normally studied by either focusing on
81 specific real-world use cases or synthetically augmenting existing datasets. Real-world cases can be
82 taken from egocentric video [53] or industrial inspection [52]. These cases present both examples
83 of the problem and detection methods, but have limited use outside of the specific environments.
84 Augmented versions of popular datasets such as MNIST and CIFAR can also be used. The works by
85 [55] and [61] focus on methods for detecting data shifts using differences between the training and
86 testing data, utilizing dimensionality reduction and statistical tests like Maximum Mean Discrepancy
87 and Kolmogorov-Smirnov test. The benefit of using synthetically augmented data for testing is that

Table 1: Existing urban computer vision stationary and changing location datasets. The *Location* can be either changing denoting moving camera like the ones on self-driving cars or stationary like on surveillance cameras. The *Type* of the datasets can be either RGB, thermal or LiDAR, the *Duration* is the size of the dataset in hours, the *Period* is the capturing time span and the *Metadata* is any additional information

Name	Year	Location	Type	Duration [hours]	Period	Metadata
KAIST [32]	2015	Changing	RGB/Thermal	43.41	-	-
CVC-14 [20]	2016	Changing	RGB/Thermal	11.8	-	-
Oxford RobotCar [48]	2017	Changing	RGB/LiDAR	-	1 year	GPS, IMU, Day/Night, Weather
Aachen Day-Night [70]	2018	Changing	RGB	-	-	GPS, Day/Night, Weather
Gated2Depth [23]	2019	Changing	RGB/LiDAR	-	-	GPS, IMU, Day/Night, Weather
Dark Zurich [68]	2019	Changing	RGB	-	-	GPS, Day/Night
ACDC [69]	2020	Changing	RGB	-	several days	GPS, Weather
Ford AV [1]	2020	Changing	RGB/LiDAR	-	1 year	GPS, IMU Day/Night, Weather, Time
Bdd100k [87]	2020	Changing	RGB	-	-	Weather, Time
UCSD [49]	2010	Stationary	RGB	3.1	-	-
Caltech Pedestrian [13]	2011	Stationary	RGB	10	-	-
VIRAT [54]	2011	Stationary	RGB	29	-	-
Avenue [46]	2013	Stationary	RGB	0.5	-	-
ShanghaiTech Campus [45]	2018	Stationary	RGB	3.6	-	-
Surveillance Videos [75]	2018	Stationary	RGB	128	-	-
Street Scene [62]	2020	Stationary	RGB	4	2 summers	-
ADOC [60]	2020	Stationary	RGB	24	1 day	-
AU-AIR [5]	2020	Stationary	RGB	2	-	Time, Positions
MEVA [12]	2021	Stationary	RGB/Thermal	144	3 weeks	GPS, Time
LTD (Our)	2021	Stationary	Thermal	298	8 months	GPS, Day/Night, Weather, Time

88 different types of shifts can easily be simulated - from gradual drift to adversarial attacks [28]. But
 89 these simulated shifts do not always correspond to real-world ones. Some more robust methods also
 90 exist [77], aimed at using real-world drift in wider variety of use cases. The need for more research
 91 into concept drift, paired with a long-term real-world dataset is evident, as the effects from it can
 92 limit long term deployment of vision systems [72, 2].

93 2.2 Datasets

94 We can separate previous work roughly in two types of use cases - datasets that contain a scenes from
 95 a stationary location, like the ones captured from CCTV and surveillance cameras and datasets with
 96 constantly changing locations, like the ones specifically directed towards autonomous cars, robots
 97 and human egocentric footage. The two types of datasets are used for different tasks, like vehicle and
 98 pedestrian detection and environmental segmentation for changing datasets [32, 87, 1] and pedestrian
 99 tracking and anomaly detection for stationary ones [45, 62, 12]. The changing datasets also benefit
 100 from more diverse data coming from different sensors, compared to more image based stationary
 101 datasets. Our proposed LTD dataset is directed towards advancing the state-of-the-art in stationary
 102 location outdoor urban datasets by providing a longer duration, larger variation and rich metadata. A
 103 comparison in Table 1 shows how the dataset stacks against previous work.

104 Datasets used for autonomous driving with changing locations [87, 70, 23, 1], which contain multiple
 105 modalities like LiDARs, RGB, depth cameras, as well as GPS and IMU data. They also contain
 106 data with longer duration from multiple days [69] to a whole year [48]. These datasets also focus
 107 on presenting adverse weather conditions, which can be used for domain adaptation and making
 108 autonomous driving and robotics application more robust [68, 1, 69]. Thermal datasets are less
 109 prevalent but still widely used [17, 20]. These moving location car datasets normally do not contain
 110 explicit information of their duration, as they are captured from many cars and the data is sampled.

111 On the other hand stationary location datasets do not contain any information about the period over
 112 which they were collected. This combined with the relative short duration of many of the widely
 113 used datasets ([49, 45, 13, 44]) makes it impossible for them to be used for studying long-term
 114 effects on deployed machine learning solutions. The duration of some of these datasets is taken from
 115 the research presented in [60]. Some larger datasets are gathered from internet videos [75], which
 116 lack the needed continuity for testing gradual concept drift in the data. More recent datasets have
 117 been produced with the goal to capture larger variations in the environments [12, 60], but with a
 118 limited scope. The lack of metadata is another problem, limiting the study of factors causing concept

119 drift, as only some of the investigated datasets provide insufficient metadata [5, 12, 66]. Most of
 120 the investigated datasets focus on RGB data, with only some containing both RGB and thermal
 121 data [32, 12]. However, thermal imaging is better at preserving preserving people’s anonymity as it
 122 does not capture facial and body detail. This removes the need for post-processing like blurring or
 123 pixelating faces to protect personal data [88, 47, 37], which is a crucial requirement for complying
 124 with the European general data protection regulations (GDPR).The thermal imaging market has seen
 125 significant growth [14] and is forecast to expand even more in the following years [65, 34], which
 126 makes it necessary for long-term public thermal datasets to be easily accessible

127 3 The Long-term Thermal Drift (LTD) Dataset

128 To address the gaps seen in the stationary surveillance state-of-the-art and to leverage the need for
 129 more thermal data, a new dataset is proposed. It consists of thermal videos with resolution 288×384
 130 captured through the period of **8 months** using a Hikvision DS-2TD2235D-25/50 thermal camera
 131 [30]. The camera is a long wavelength infrared (LWIR) unit, capturing wavelengths between 8 and 14
 132 μm . Raw data is captured through the day and saved in a mp4 format as 8-bit uncalibrated grayscale
 133 videos. A pre-processing algorithm is then run through the data. It first cuts the raw files into days
 134 starting from 00 : 00 and separates them into folders. Each folder is timestamped with the year,
 135 month and day timestamp. The videos for each day are then cut into **2-minute** clips selected every
 136 30 minutes through the day, for a total of **298 hours**. These videos are additionally timestamped with
 137 hour and minute timestamp. The starting point of the data is May 2020 until September 2020, together
 138 with a second part from January 2021, up until May 2021. This gives the data a large weather variation
 139 through the winter, spring and summer seasons. The images were taken on the harbor front in Aalborg,
 140 Denmark. The approximate longitude and latitude coordinates are given as (9.9217, 57.0488).
 141 We provide the dataset - <https://www.kaggle.com/ivannikolov/longterm-thermal-drift-dataset>,
 142 together with the code to extract the necessary data and to reproduce the experimental pipeline
 143 <https://github.com/IvanNik17/Seasonal-Changes-in-Thermal-Surveillance-Imaging>.

144 Some examples of seasonal and day and night variation of the captured data, together with weather
 145 and human activity variation can be seen in Figure 1. These large variations, together with a total size
 146 almost twice as large as other datasets in Section 2.2, allows for studying the effects of concept drift
 147 on trained models.

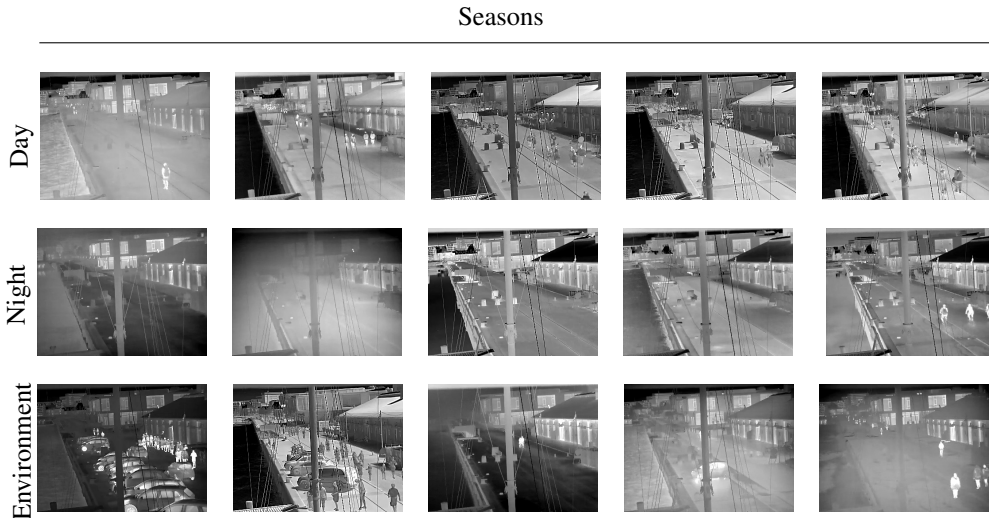


Figure 1: Examples of extreme changes in the image data contained in the proposed dataset. From left to right the day and night rows show example changes from data of February, March, April, June and August. The third row shows changes based on weather conditions and human activity.

148 Figure 1 depicts issues stemming from the natural thermal data concept drift, such as grayscale
 149 inversion in the background and people in different seasons, view limitation and reflections caused by
 150 weather like fog, rain, snow, view cluttering from multiple people and vehicles.

Table 2: Average metadata for each month. From left - temperature, humidity, precipitation, dew point, wind direction, wind speed, sun radiation and minutes of sunshine in a 10-minute interval.

	Temp. [°C]	Hum. [%]	Precip. [kg/m ²]	Dew P. [°C]	Wind Dir. [degrees]	Wind Sp. [m/s]	Sun Rad. [W/m ²]	Sun [min]
Jan.	-0.48	90.10	0.01	-1.96	161.91	2.58	23.97	0.90
Feb.	-0.54	85.15	0.01	-2.83	131.00	2.95	51.12	1.42
Mar.	3.75	83.61	0.01	0.93	218.80	3.58	99.35	1.85
Apr.	4.47	97.25	0.13	4.10	126.50	2.97	67.31	2.23
May	10.74	75.46	0.01	6.07	217.32	3.04	256.76	3.66
June	16.36	71.46	0.01	10.57	151.27	2.37	256.46	3.63
July	12.91	75.32	0.01	8.46	268.15	3.97	270.17	3.62
Aug.	16.93	79.17	0.02	12.69	163.18	2.08	197.86	3.15

151 3.1 Metadata Analysis

152 Besides video data we also provide metadata in the form of weather data, gathered using the open
 153 source Danish Meteorological Institute (DMI) weather API [33] in 10-minute intervals. The selected
 154 properties are - temperature, measured in [°C], relative humidity percentage measured 2m over
 155 terrain, accumulated precipitation in [kg/m²], dew point temperature in [°C] measured 2m over
 156 terrain, wind direction in degrees orientation, wind speed in [m/s], both measured 10m over terrain,
 157 mean sun radiation in [W/m²] and minutes of sunshine in the measured interval. These properties
 158 are selected, as it is speculated that they would be useful to explain changes in the captured image
 159 data. An overview of the average weather metadata measurements of the dataset can be seen in Table
 160 2. Temperature and relative humidity have been shown to affect thermal cameras, when detecting
 161 surface defects in concrete structures [80], measuring skin temperature changes on athletes [35],
 162 getting accurate readings for volcanology [3] and inspecting food [21]. Precipitation and dew point
 163 temperature can indicate the presence of rain, fog or high moisture and condensation. These can
 164 increase attenuation of infrared light and change the produced camera response [4, 11]. The build-up
 165 of moisture can create puddles in the images, which would change the scene reflectivity and reflected
 166 temperature [7]. The sun radiation and amount of sunshine can affect the captured images by rapidly
 167 changing the intensity of the infrared light. Finally wind speed and direction can cause movement of
 168 background parts of the scene like water ripples, ropes, etc., as well as movement of the camera itself.

169 4 Long-term Performance Experiment

170 We study the effects of concept drift on six machine learning models - two autoencoders, two object
 171 detectors and anomaly detectors. For these experiments only weather parameters not found to have
 172 significant correlation to other parameters are considered, namely - temperature, humidity, wind speed,
 173 wind direction and precipitation. More information on the correlation between weather parameters is
 174 given in the Appendix.

175 4.1 Data Selection Protocol

176 In order to keep the experiments and labelling effort manageable, samples across the full data set
 177 are selected based on the following protocol. This is done to minimize the number of frames and
 178 maximize the variation covered by the selection. For the sampling temperature metadata is used, as
 179 it is proven to directly correlate with changes to thermal images [80, 35, 21]. The protocol can be
 180 summarized as follows:

- 181 1. Every **2-minute** clip in the dataset is sampled with a frequency of one frame per second,
 182 resulting in **120 frames per clip**;
- 183 2. Based on the temperature metadata, we select a cold month for the training set and another
 184 cold month, a median temperature one, and a warm month for the test set;
- 185 3. The training set exists in three variants: coldest day 13th of February, the corresponding
 186 week 13-20 of February, and the entirety of February;
- 187 4. The test sets consist of data from January (similar cold month), April (month with median
 188 temperature), and August (warmest month).

189 From each of the thus created subsets, a greedy furthest point sampling is used for selecting frames.
190 The frames for each day are sampled by calculating the farthest distances in the 2D feature space
191 of the frame numbering and the temperature. A visual example of the sampling can be seen in
192 the Appendix. The amounts of selected samples vary for the training data depending on the used
193 algorithm. This is further discussed in the next sections.

194 4.2 Tested Models

195 Six deep learning models are tested. All six are originally designed to work with RGB data, so their
196 input channel is reduced from 3 to 1, corresponding to a change to the grayscale thermal data. No
197 additional changes were made, as the focus of the paper is not algorithm performance but change in
198 performance over time.

199 Two of tested models are autoencoders, as representatives for dimensional reduction, noise removal,
200 concept drift detection and anomaly detection methods. Autoencoders are well suited for researching
201 concept drift in long-term datasets, as their reconstruction performance is inherently tightly connected
202 to the training data. The first autoencoder follows a simple fully convolutional architecture with
203 symmetric 5-layer encoder and decoder. The implementation is based on the autoencoder used in a
204 previous work [43]. It is theorized that its simplicity will make it sensitive to concept drift in the input
205 data. The second autoencoder is the latest version of the Vector Quantised Variational Autoencoder
206 (VQVAE2) [63]. This autoencoder uses collections of multi-scale hierarchical discrete tensors, called
207 codebooks, to map its latent space. This gives it more robustness compared to regular autoencoders.
208 The VQVAE2 implementation used here is closely based on [50]. Both autoencoders are trained for
209 200 epochs.

210 Two versions of the anomaly detector method MNAD [57] are also tested. They extend traditional
211 autoencoders, by introducing memory-guided normality detection. We look at the typical reconstruc-
212 tion based comparison (MNAD_recon), as well as the prediction approach (MNAD_pred), using
213 the preceding four consecutive frames to predict the future frame. The backbone consists of the
214 U-Net structure, without skip-connections for the MNAD_recon variant. In between the encoder and
215 decoder of U-Net is a memory module, storing prototypical events, concatenated with the original
216 encoder output. The memory is primarily learned during training, but also updates during testing.
217 Both versions are trained for 100 epochs.

218 Lastly two supervised object detectors are also tested - the YOLOv5 and Faster R-CNN[64]. The
219 chosen hyperparameters for YOLOv5 remain the same as the work in [82], except that the initial
220 learning rate is set to 0.00075 and trained for 200 epochs. The Faster R-CNN is trained for 200
221 epochs as well with SGD, with initial learning rate set as 0.005, the weight decay as 0.005 and the
222 momentum kept at 0.9. Both object detectors have previously been successfully applied to outdoor
223 thermal imaging [38, 31, 9, 18].

224 The autoencoders are trained on a NVIDIA GTX1070 Super, the anomaly detectors on a NVIDIA
225 RTX3080 and the object detectors on a NVIDIA RTX2080Ti.

226 4.3 Drift Algorithmic Performance Analysis

227 This experiment aims to see how the performance of the selected algorithms changes depending on
228 the variation of the training data.

229 The training sets for the autoencoders and the anomaly detectors contain 5000 frames per subset, sam-
230 pled using the method discussed in subsection 4.1, where 20% are used for validation. Performance
231 is reported as the average MSE across every image in each of the three test sets. The performance of
232 the two autoencoders and anomaly detectors is listed in Table 3. We can see that the MSE for the
233 CAE, VQVAE2 and MNAD_recon increases the farther away the test data goes from the training data.
234 It can also be seen that the larger temporal pool provided for sampling for the weekly and monthly
235 training data helps with keeping the MSE lower through the different months. The MNAD_pred is
236 the only model keeping a consistent performance through the months without any noticeable drift.
237 This is most likely due to the U-Net skip connections being able to reconstruct the background scene
238 with a very low reconstruction error.

239 For the object detectors, because of the necessary data-labeling a smaller number of images are
240 used for training and testing - both having 100 frames per subset. In addition to these a validation

241 set comprising of 51 images evenly sampled from a previous annotated dataset [43] collected in
 242 February 2020 is used. All of the subsets are annotated with bounding boxes around people seen
 243 in each frame using the LabelImg open source program [81]. The annotations are also part of the
 244 LTD dataset. Since the performance of object detector is based on detected bounding boxes, mAP is
 245 used to evaluate it. The performance of the object detectors is given in Table 4. The accuracy of both
 246 object detectors, drastically drops in the month of April. To prevent overfitting the smaller amount of
 247 training data, we observe the validation and test loss.

248 As a conclusion from the performance analysis the higher variation provided by sampling from
 249 the week and month data, has been translated to better and more stable models in all the tested
 250 models. We can still see the effects of the seasonal drift, so additional analysis will be provided in the
 251 following sections.

Table 3: Results are reported as the average of the MSE across every frame in the test set. Higher results show worse performance.

Methods	Train		Test	
	Feb.	Jan.	Apr.	Aug.
CAE	Day 5k	0.0096	0.0202	0.0242
	Week 5k	0.0061	0.0167	0.0212
	Month 5k	0.0042	0.0109	0.0147
VQVAE2	Day 5k	0.0051	0.0072	0.0068
	Week 5k	0.0039	0.0066	0.0061
	Month 5k	0.0021	0.0039	0.0035
MNAD Recon.	Day 5k	0.0028	0.0057	0.0069
	Week 5k	0.0065	0.0066	0.0062
	Month 5k	0.0015	0.0041	0.0048
MNAD Pred.	Day 5k	0.0008	0.0007	0.0009
	Week 5k	0.0007	0.0006	0.0007
	Month 5k	0.0007	0.0006	0.0007

Table 4: Results are reported as the mAP₅₀ across every frame in the test set. Lower results show worse performance.

Method	Train		Test	
	Feb.	Jan.	Apr.	Aug.
YOLOv5	Day 100	0.8010	0.5390	0.5240
	Week 100	0.7940	0.4540	0.4860
	Month 100	0.7930	0.4860	0.4830
Faster R-CNN	Day 100	0.6760	0.3230	0.3370
	Week 100	0.6740	0.2790	0.3060
	Month 100	0.6400	0.2560	0.3180

252 5 Drift Analysis

253 In this section we look at the possible relations between the observed model performance drift and
 254 the changes in the captured metadata. Looking through the data examples given in Figure 1, two
 255 main visual change types are identified - seasonal and day/night. These types can be caused by either
 256 changes in the weather conditions, the human activity or a combination between the two. The relation
 257 between the model performance metrics and metadata features representing these changes is analysed.
 258 As discussed in section 3.1, we choose temperature, humidity, precipitation, wind direction and wind
 259 speed as weather data features. For analysing the day/night changes the timestamp data is used to
 260 calculate hours of the day, as well as to calculate the sunrise and sunset times [74, 51]. To quantify
 261 the activity in the scene the difference between each testing frame and the previous frame from the
 262 main dataset is calculated. The mean value from this difference is selected. To focus only on scene
 263 activity everything in the background that moves like the waterfront and the visible ropes and masts
 264 is masked out. More information on this can be found in the Appendix.

265 We choose to use the results only from the models trained on the monthly February data, for easier
 266 visualization. The correlation between each of these features and the measured performance metric
 267 for each of the methods is first calculated. For the autoencoders and anomaly detectors this is the
 268 MSE, while for the object detectors we calculate the F1-score from all images containing people, as it
 269 gives a good overview of the precision and recall of the models. Both the basic Pearson’s correlation,
 270 as well as the more sensitive to non-linear relations Distance correlation [78, 16] are calculated. The
 271 statistical significance p-values are also calculated with threshold at 0.05. The calculated correlation
 272 r values are given in Table 5, where those with p-values below the threshold are shown in red.

273 From Table 5 it can be seen that temperature and humidity have both the largest correlation values to
 274 most of the metrics, as well as the most consistently statistically significant results, followed by the
 275 scene activity and day/night features. We focus on these four features in the following analysis.

276 To get a better understanding of not only the correlational, but also causal relations between the
 277 models’ performance metrics and the chosen features, we look at the Granger causality test [22].

Table 5: Correlation between the model’s measured performance values MSE and F1-score and the weather, time and scene activity features. Two correlation measures are used - Pearson’s (P.C.) and Distance (D.C.) correlation. Measures which do not meet the statistical significance threshold of their p-values are shown in red and marked **X**. The Day/Night features is specified as D./N.

	Measure	Temp.	Hum.	Wind Dir.	Wind Sp.	Precip.	Activ.	D./N.	Hour
CAE - MSE	P. C.	0.679	0.636	0.018 X	0.157	0.109 X	0.270	0.545	0.166
	D. C.	0.682	0.588	0.158	0.170	0.126 X	0.291	0.538	0.287
VQVAE2 - MSE	P. C.	0.381	0.690	0.001 X	0.194	0.172	0.217	0.403	0.124
	D. C.	0.347	0.639	0.174	0.201	0.224	0.217	0.382	0.213
MNAD Recon. - MSE	P. C.	0.607	0.672	0.016 X	0.173	0.126	0.220	0.509	0.156
	D. C.	0.617	0.629	0.188	0.177	0.155	0.252	0.501	0.273
MNAD Pred. - MSE	P. C.	0.107 X	0.277	0.064 X	0.152	0.072 X	0.677	0.369	0.137
	D. C.	0.231	0.348	0.154	0.172	0.086 X	0.665	0.462	0.312
YOLOv5 - F1-score	P. C.	0.261	0.258	0.102 X	0.011 X	0.096 X	0.124 X	0.047 X	0.009 X
	D. C.	0.293	0.283	0.146 X	0.094 X	0.135 X	0.255	0.113 X	0.174 X
Faster R-CNN - F1-score	P. C.	0.354	0.456	0.115 X	0.135 X	0.0124 X	0.199	0.147	0.001 X
	D. C.	0.334	0.460	0.228	0.149 X	0.065 X	0.231	0.163	0.118 X

278 The test only guarantees a predictive causality between variables, but would be able to point out
 279 any possible connections. The Granger causality tests the null hypothesis that the past values of one
 280 variable do not cause another. The p-value threshold is set to 0.05, below that the null hypothesis
 281 can be rejected, with the conclusion that there is a predictive causality between the variables. As the
 282 normal Granger causality test as presented in [71] is used on data with linear relations, we also use
 283 the more robust non-linear Neural Granger test [79]. Two best performing versions are used, based
 284 on long-short term memory networks (LSTM) and multi-level perceptron (MLP). Both models were
 285 trained using proximal gradient descent [56], with $\lambda = 0.002$, ridge regression coefficient 0.01 and
 286 learning rate of 0.005. The results from the Granger causality tests are given in Table 6, where cells
 287 shown with green indicate a statistically significant presence of Granger causality and the ones with
 288 red - no presence.

Table 6: Results from calculating linear and non-linear (LSTM and MLP) Granger causality tests. The cells marked with **✓** show positive predictive causality, while cells marked with **X** show no significant causality.

	Temp.			Hum.			Activ.			D./N.		
	Basic	LSTM	MLP	Basic	LSTM	MLP	Basic	LSTM	MLP	Basic	LSTM	MLP
CAE - MSE	✓	✓	✓	✓	✓	X	X	X	X	✓	✓	✓
VQVAE2 - MSE	✓	✓	✓	✓	✓	X	X	X	X	✓	✓	✓
MNAD Recon. - MSE	✓	✓	✓	✓	✓	X	X	X	X	✓	✓	✓
MNAD Pred. - MSE	✓	✓	X	X	X	X	X	✓	X	✓	✓	✓
YOLOv5 - F1-score	✓	X	X	✓	X	✓	X	X	X	X	X	X
Faster R-CNN - F1-score	X	X	X	X	✓	X	X	X	X	✓	✓	✓

289 The results show that the human activity has no predictive causality towards the performance of the
 290 models, which combined with the results from the correlation analysis, can point towards a second-
 291 hand relation. Our hypothesis is that the change in weather conditions and the day/night cycle are
 292 related to the change in human activity. From the other features, temperature has stronger predictive
 293 causality towards the autoencoders and anomaly detectors, while humidity and the day/night cycle
 294 have a more balanced predictive causality.

295 Figure 2 shows the relationship between the features and the model metrics. As a processing step
 296 before plotting the temperature and humidity they are first smoothed using a mean filter with a kernel
 297 size of 20 and then the MSE is normalized between 0 and 1. This is done as they are not compared,
 298 but the trend of their change is visualized. We plot the average values for the training month of
 299 February, as a vertical red line, to indicate a "threshold".

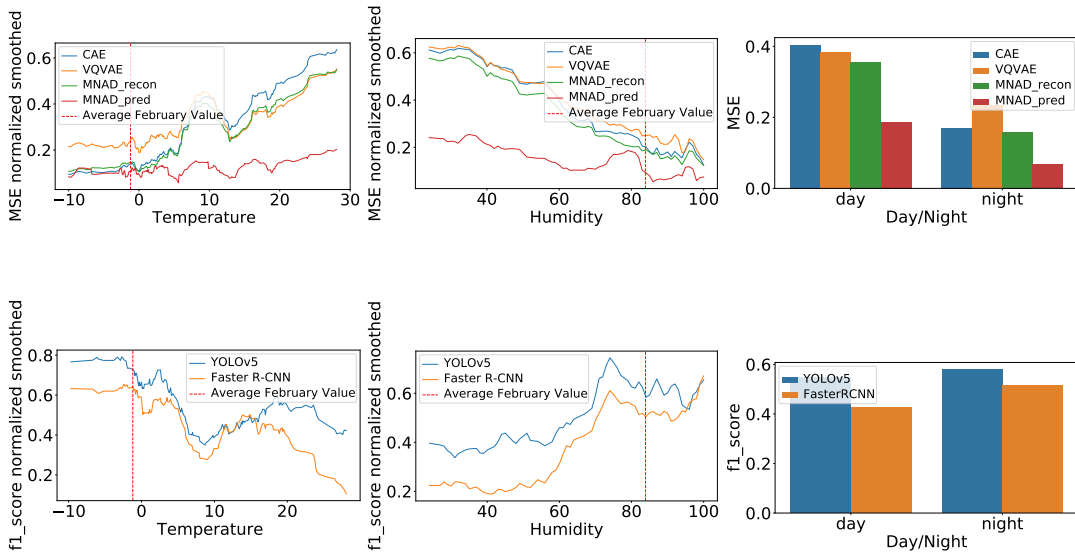


Figure 2: Visual representation of the changes of MSE and F1-score for the tested models compared to the temperature, humidity and day/night cycle.

300 6 Drift Prediction Baseline

301 As a baseline for exploring and mitigating the effects of concept drift a reference algorithm for
 302 predicting drift is presented. We use three strongest features - temperature, humidity and day/night
 303 cycle, together with MSE from our convolutional autoencoder (CAE) trained on the February monthly
 304 data. The CAE is chosen, as it is the most sensitive to changes in the dataset and is strongly correlated
 305 to the performance of all other tested models, except Faster R-CNN. The CAE MSE results from
 306 the training data are used together with the chosen features to train two widely used novelty/outlier
 307 detection models - isolation forests [42] and one-class SVM [59], available as part of scikit-learn
 308 [58]. The isolation forest has 100 base estimators, the one-class SVM has a radial basis function
 309 (RBF) kernel and γ of 0.03. We then test the results from each day from the full LTD dataset to detect
 310 points where many outliers emerge in both predictors. The first large concentration of outliers in 7
 311 consecutive days is selected, which in our case is 5th of March.

312 To test if taking in consideration data from the found drift point can help with the performance of the
 313 models against concept drift, training data from one week starting after the 5th of March is sampled.
 314 The new data is used together with the previous training data from February to retrain the tested
 315 models. The results, together with the month results from Table 3 and 4 for comparison, are given in
 316 Table 7 and Table 8. By adding the March data, all tested models achieve better results. We can see
 317 that the outlier detection models trained on the CAE MSE, together with the temperature, humidity
 318 and day/night cycle can be used together as a indicator for the amount of drift present in the input
 319 data.

320 7 Conclusion and Future Work

321 In this paper we introduced the Long-term Thermal Drift (LTD) dataset spanning 8 months for
 322 detecting concept drift in deep learning models. The dataset and the accompanying metadata can be
 323 used to document performance degradation as data drifts from the training set. These effects were
 324 studied on anomaly and object detection models, as well as autoencoders. It was demonstrated that
 325 more diverse training data lowers the effects of concept drift. The performance of the models showed
 326 a strong correlational and causal relationship to the change in temperature and humidity. A less
 327 pronounced relationship was observed to the day/night cycle and scene activity. Lastly, we showed

Table 7: The MSE results from the full month in Table 3, compared to the ones using the new training datasets containing a combination of February and the week in March where drift is detected. Higher results show worse performance.

Methods	Train	Test		
		Jan.	Apr.	Aug.
VQVAE2	Feb. 5k	0.0021	0.0039	0.0035
	Feb. 5k + Mar. 5k	0.0020	0.0033	0.0030
MNAD	Feb. 5k	0.0015	0.0041	0.0048
Recon.	Feb. 5k + Mar. 5k	0.0006	0.0015	0.0025
MNAD	Feb. 5k	0.0007	0.0006	0.0007
Pred.	Feb. 5k + Mar. 5k	0.0007	0.0005	0.0006

Table 8: The mAP₅₀ Results from the full month in Table 4, compared to the ones using the new training datasets containing a combination of February and the week in March where drift is detected. Lower results show worse performance.

Method	Train	Test		
		Jan.	Apr.	Aug.
YOLOv5	Feb. 100	0.7930	0.4860	0.4830
	Feb. 100 + Mar. 100	0.8690	0.6640	0.6110
Faster	Feb. 100	0.6400	0.2560	0.3180
R-CNN	Feb. 100 + Mar. 100	0.6990	0.3910	0.3380

328 how the concept drift can be further mitigated by detecting when it starts to manifest and providing
 329 additional data to the training process.

330 The proposed LTD dataset contains a combination of diverse environmental images and granular
 331 metadata. The equally spaced long-term data can be used to test the change in performance of deep
 332 learning models at different data scenarios - only day or night data, changes between activity in the
 333 weekday and weekends, summer and winter scenarios. The influence of weather conditions like rain,
 334 snow or fog can also be explored. The possibility of training more robust models and predicting
 335 when steps need to be taken, before their performance degrades, is only possible with such long-term
 336 sequential datasets.

337 Possible negative social impacts of such long-term datasets concentrating on a single location is that
 338 they can be used to track the habits, interactions and movements of people. We offset this by providing
 339 a thermal dataset, which provides greater protection of people’s anonymity than conventional RGB
 340 and does not require post-processing for blurring facial features.

341 The long-term nature of the dataset can also be used, as demonstrated in this paper, to utilize time-
 342 series analysis procedures on the outputs from different layers of deep learning models. From simple
 343 time-series analysis and forecasting models like Vector Autoregressive (VAR) Models [29] to more
 344 complex and data agnostic models like STRIPE [25] or Adversarial Sparse Transformers [84].

345 We believe that the proposed dataset and the accompanied analysis would help researchers understand
 346 the causes for performance drift in models and hence enable easier deployment of long-term solutions
 347 in outdoor environments.

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