

Appendix: Guided Stable Dynamic Projections

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1. PCD-tSNE parameters

Table 1 presents the PCD-tSNE parameters used for each dataset. This table complements Sec. 3.2 of the main text.

dataset	λ	PC scaling
cartolastd	10^{-2}	10^0
cifar10cnn	10^{-5}	10^0
esc50	10^{-2}	10^{-1}
fashion	10^{-4}	10^{-1}
gaussians	10^{-3}	10^1
nnsset	10^{-3}	10^0
qtables	10^{-3}	10^{-1}
quickdraw	10^{-3}	10^0
sorts	10^{-1}	10^0
walk	10^{-4}	10^0

Table 1: The λ parameter modulates the amount of global influence applied to points in $P(\mathbf{D}^t)$; the PC scaling term scales W to increase/decrease the area of global influence, i.e., it scales the principal components of \mathbf{D} .

2. LD-tSNE parameters

Table 2 presents the LD-tSNE parameters used for each dataset. This table complements Sec. 3.1 and Sec. 5.5 of the main text.

dataset	λ	β	α	\mathbf{L}^I projection (# landmarks)
cartolastd	.2	2	4	PCA(N)
cifar10cnn	.5	4	1	tSNE(N)
esc50	.3	5	1	PCA(N)
fashion	.1	4	2	tSNE(N)
gaussians	-	-	-	PCA(N)
nnsset	.02	8	1	PCA(N)
qtables	-	-	-	PCA(N)
quickdraw	.1	2	1	tSNE(N)
sorts	.25	10	2	PCA(NT)
walk	-	-	-	PCA(N)

Table 2: The λ , α , and β parameters control the amount of influence landmarks have on the points being projected. In simple terms, α controls the tightness of clusters in $P(\mathbf{D}^t)$, β scales the strength of the “pull” of landmarks \mathbf{L} on points in $P(\mathbf{D}^t)$, and λ balances the two factors. Values marked “-” were obtained using the interactive mode that was implemented and gave the user real-time control over parameters during the optimization. N is the number of points in \mathbf{D}^t and T is the total number of timesteps in \mathbf{D} .

3. Metric results

Table 3 shows unaggregated metric results. Each of the 10 subtabels correspond to a dataset, columns correspond to the different quality metrics, and the rows represent the different methods. Methods are ordered according to their strategy: Per-timeframe, Global, Continuous, and Guided. The columns correspond, respectively, to distance preservation metrics ($S_{Pearson}, S_{Spearman}, S_{Kendall}, S_{Stress}$), neighborhood preservation metrics ($S_{NH}, S_{NP}, S_{Trust}, S_{Cont}$), and temporal stability metrics ($T_{Pearson}, T_{Spearman}, T_{Kendall}, T_{Stress}$). The colormap is normalized independently for each metric and each dataset.

These tables complement Sections 5.2 and 5.3 of the main text.

	$S_{Pearson}$	$S_{Spearman}$	$S_{Kendall}$	S_{Stress}	S_{NH}				S_{NP}				S_{Trust}				S_{Cont}				$T_{Pearson}$				$T_{Spearman}$				$T_{Kendall}$												
					T_{PCA}	TF_{PCA}	TF_{ISNE}	TF_{UMAP}	G_{AE}	G_{VAE}	G_{PCA}	G_{ISNE}	G_{UMAP}	C_{TSNE}	C_{UMAP}	D_{TSNE}	PCD_{TSNE}	LD_{TSNE}	T_{PCA}	TF_{PCA}	TF_{ISNE}	TF_{UMAP}	G_{AE}	G_{VAE}	G_{PCA}	G_{ISNE}	G_{UMAP}	C_{TSNE}	C_{UMAP}	D_{TSNE}	PCD_{TSNE}	LD_{TSNE}									
cartolastd	0.931	0.928	0.790	0.137	0.505	0.480	0.937	0.876	0.761	0.570	0.450	0.477	0.601	0.075	0.055	1.876	0.864	0.987	0.917	0.270	0.307	0.175	0.132	1.384	0.344	-0.11	-0.08	1.911	0.141	-0.03	-0.02	1.716	0.772	0.704	0.565	0.454	0.574	0.392	0.301	0.851	
cifar10cnn	0.756	0.800	0.615	0.487	0.597	0.592	0.947	0.913	0.661	0.04	-0.04	-0.03	2.003	0.576	0.556	0.908	0.893	0.758	0.985	0.908	0.482	0.778	0.987	0.916	0.442	0.514	0.788	0.655	0.970	0.366	0.368	0.282	1.267	0.636	0.599	0.559	0.804	0.816	0.889	0.720	0.367
esc50	0.634	0.693	0.520	0.731	0.576	0.556	0.908	0.893	0.758	0.985	0.908	0.482	0.864	0.618	0.950	0.934	0.778	0.987	0.916	0.442	0.514	0.788	0.655	0.970	0.366	0.368	0.282	1.267	0.636	0.599	0.559	0.804	0.816	0.889	0.720	0.367					

