

# Feb Log

February 2, 2021

## 1 1/31

### 1.1 Chess

*Remark 1.* A blunder free game with weak positional moves:

<https://www.chess.com/analysis/game/live/6409740211?tab=analysis>

*Remark 2.* A complicated blunder filled game:

<https://www.chess.com/a/CbAJ8Wm4XAX8>

To Analyze:

### 1.2 Complex Analysis

## 2 2/1

### 2.1 Chess

*Remark 3.* Talk about a clean game:

<https://www.chess.com/a/Gzp6PJxWXAX8>

*Remark 4.* My first brilliant move!:

<https://www.chess.com/a/2BfrDrz2JXAX8>

## 2.2 Technical Animation

*Interesting 1.* TA Arjun is interested in PDEs and numerical simulation.

*Remark 5.* Course Website:

<http://graphics.cs.cmu.edu/nsp/course/15464-s21/www/>

*Computer Animation: Algorithms and Techniques* is the course textbook. In drive.

*Question 1.* Does greater physical simulation accuracy lead to a less palatable viewing experience?

*Answer 1.* Not sure but often directors will personify animations and we have different parameters to give different personifications. For example "angry storm".

*Answer 2.* It seems exaggerated motion is often more digestible (think actors for example). Often used actors in motion capture

*Interesting 2.* Rig Net: automatically rigging meshes. Note: rigging is process of jointing meshes, providing structure/skeleton.

*Remark 6.* Beginning of rigging: find medial axis of geometry and impose some structure.

## 2.3 On Lp Brunn-Minkowski Type Inequalities

**Tag:** BrunnMinkowski

*Remark 7.*  $V$  is  $1/n$  concave measure w.r.t Minkowski sum. Need normalizing  $1/n$  powers

**Prop 1.**

$$h_{K+L}(u) = h_K(u) + h_L(u)$$

*Remark 8.* **Brascamp-Lieb**

$\alpha \geq -1/n, t \in [0, 1]$ . With  $f, g, h : \mathbb{R}^n \rightarrow \mathbb{R}_+$  satisfy

$h((1-t)x + ty) \geq [(1-t)f(x)^\alpha + tg(y)^\alpha]^{1/\alpha}$  then

$$\int_{\mathbb{R}^n} h(x) dx \geq [(1-t)(\int_{\mathbb{R}^n} f(x) dx)^{\alpha/1+n\alpha} + t(\int_{\mathbb{R}^n} g(x) dx)^{\alpha/1+n\alpha}]^{1+n\alpha/\alpha}$$

Prekopa Lindler is  $\alpha = 0$

**Prop 2.**

$$(1-t)X_s 1_A \oplus_s tX_s 1_B = 1_{(1-t)A+tB}$$

*Remark 9.* Changing operator: Minkowski sum, to  $l_p$  variants.

*Remark 10.* Also some kind of interplay between functional inequalities and volume inequalities. Between supremal convolutions and Lp Minkowski sums.

## 2.4 PDEs and Data Analysis

**TAG:** OptimalTransport

*Theme 1.* The more assumptions you make on a measure the better approximation you can achieve

*Interesting 3.* Shimaa is interested in stochastic BDEs. Wes interested in foundations of machine learning.

*Theme 2.* Look at a measure as some kind of energy landscape and the transport map as the process of rearranging mass.

*Remark 11.* Often transportation cost is  $|x - y|^p$ .

*Remark 12.* Optimal transport minimizes transportation cost.

*Theme 3.* Goal is to find weaker problem which provides good solution to wider class of subproblems.

## 3 2/2

### 3.1 Goals

1. Chess: 1300 in blitz
2. Research: 3 hours worked, some progress, email tkocz
3. Thesis: 5 pages
4. Homework: Animation
5. Get glenn to agree to a time

### 3.2 DRL

**TAG:** DRL

*Question 2.* what is computational design?

*Remark 13.* Course link:

[https://cmudeeprl.github.io/403\\_website/](https://cmudeeprl.github.io/403_website/)

*Remark 14.* Katerina F.

"My genes have strong priors from the world"

*Remark 15.* Inconsistent rewards lead to addiction.

*Remark 16.* For a long time large emphasis on discovering new behaviors in DRL. Now thinking we need to develop behavior repertoire and associate with some stimuli.

*Remark 17.* Curiosity, a desire to see new things, very intrinsically powerful.

*Remark 18.* Conor Igoe:

For a fixed known opponent, the evolution of chess is markovian from the perspective of the player.

In some cases (such as driving) we need multiple frames/time steps to even attempt to play. But this can also be redefined as markovian by letting states correspond to multiple time steps.

*Remark 19.* Model vs. non-model based. Can we learn via simulation or not.

*Remark 20.* Cannot use gradient based optimization often in DRL. We can if we have a model.

### 3.3 The Embodiment Hypothesis

*Remark 21.* Link:

[https://cogdev.siteshost.iu.edu/labwork/6\\_lessons.pdf](https://cogdev.siteshost.iu.edu/labwork/6_lessons.pdf)

*Remark 22.* The six lessons from child development:

1. Be multimodal

### 3.4 Modeling Evolution

*Remark 23.* Selection or drift: tug of war between determinism and randomness.