Quantifying Uncertainty Advanced Artificial Intelligence: Lecture

Heriberto Cuayáhuitl http://staff.lincoln.ac.uk/hcuayahuitl

School of Computer Science, University of Lincoln



2 October 2019

L

About Me



- Dr. Heriberto Cuayáhuitl
- PhD in informatics, University of Edinburgh, UK
- Research Interests:
 - Machine Intelligence
 - Dialogue Systems
 - ► Interactive Robots
- ▶ Surgery Hours: Wednesday 13:00-14:00, or arrange meeting
- ▶ Office Location: Isaac Newton Building, room INB3130
- ► Email: HCuayahuitl@lincoln.ac.uk

Overview

Topics:

- ▶ Introduction to Probability
- Probabilistic Reasoning

Readings:

- Russel, S.& Norvig, P. (2013). "Artificial Intelligence: A Modern Approach", chapter13 (main reading)
- Bishop, C. "Model-Based Machine Learning", chapter1 (optional reading)

Let Ω be the **sample space**, e.g., 6 possible rolls of a die, and $\omega \in \Omega$ a **sample point** or **possible world** or **atomic event**

- ▶ Let Ω be the **sample space**, e.g., 6 possible rolls of a die, and $\omega \in \Omega$ a **sample point** or **possible world** or **atomic event**
- A probability space or probability model is a sample space with an assignment $P(\omega)$ for every $\omega \in \Omega$ s.t. $0 \le P(\omega) \le 1$ $\sum_{\omega} P(\omega) = 1$, e.g. P(1) = P(2) = P(3) = P(4) = P(5) = P(6) = 1/6

- Let Ω be the **sample space**, e.g., 6 possible rolls of a die, and $\omega \in \Omega$ a **sample point** or **possible world** or **atomic event**
- A probability space or probability model is a sample space with an assignment $P(\omega)$ for every $\omega \in \Omega$ s.t. $0 \le P(\omega) \le 1$ $\sum_{\omega} P(\omega) = 1$, e.g. P(1) = P(2) = P(3) = P(4) = P(5) = P(6) = 1/6
- ▶ An **event** *A* is any subset of Ω, where $P(A) = \sum_{\omega \in A} P(\omega)$ e.g. P(die roll < 4) = P(1) + P(2) + P(3) = 1/6 + 1/6 + 1/6 = 1/2

- Let Ω be the **sample space**, e.g., 6 possible rolls of a die, and $\omega \in \Omega$ a **sample point** or **possible world** or **atomic event**
- A probability space or probability model is a sample space with an assignment $P(\omega)$ for every $\omega \in \Omega$ s.t. $0 \le P(\omega) \le 1$ $\sum_{\omega} P(\omega) = 1$, e.g. P(1) = P(2) = P(3) = P(4) = P(5) = P(6) = 1/6
- ▶ An **event** *A* is any subset of Ω, where $P(A) = \sum_{\omega \in A} P(\omega)$ e.g. P(die roll < 4) = P(1) + P(2) + P(3) = 1/6 + 1/6 + 1/6 = 1/2
- Variables in probability theory are called random variables, their names begin with an uppercase letter (e.g. Die₁={1,...,6}, and have domain values (e.g. {true, false})

► Think of a proposition as an event (set of sample points) where the proposition is true

- ► Think of a proposition as an event (set of sample points) where the proposition is true
- Given Boolean random variables A and B:
 - event $a = \text{set of sample points where } A(\omega) = true$
 - event $\neg a = \text{set of sample points where } A(\omega) = \text{\it false}$
 - event $a \wedge b = \text{points}$ where $A(\omega) = true$ and $B(\omega) = true$

- ► Think of a proposition as an event (set of sample points) where the proposition is true
- Given Boolean random variables A and B:
 - event $a = \text{set of sample points where } A(\omega) = true$
 - event $\neg a = \text{set of sample points where } A(\omega) = \text{\it false}$
 - event $a \wedge b = \text{points}$ where $A(\omega) = true$ and $B(\omega) = true$
- Sample points are defined by the values of random variables, i.e. the sample space is the Cartesian product of their ranges

- ► Think of a proposition as an event (set of sample points) where the proposition is true
- ▶ Given Boolean random variables A and B:
 - event $a = \text{set of sample points where } A(\omega) = true$
 - event $\neg a = \text{set of sample points where } A(\omega) = \text{\it false}$
 - event $a \wedge b = \text{points}$ where $A(\omega) = true$ and $B(\omega) = true$
- Sample points are defined by the values of random variables,
 i.e. the sample space is the Cartesian product of their ranges
- ▶ Proposition = disjunction of atomic events in which it is true, e.g. $(a \lor b) \equiv (\neg a \land b) \lor (a \land \neg b) \lor (a \land b)$ ⇒ $P(a \lor b) = P(\neg a \land b) + P(a \land \neg b) + P(a \land b)$

Syntax for Propositions

► **Boolean** random variables e.g., *Cavity* (do I have a cavity?) *Cavity* = *true* is a proposition, also written *cavity*

Syntax for Propositions

- Boolean random variables
 e.g., Cavity (do I have a cavity?)
 Cavity = true is a proposition, also written cavity
- Discrete random variables (finite or infinite)
 e.g., Weather is one of < sunny, rain, cloudy, snow >
 Weather = rain is a proposition
 Values must be exhaustive and mutually exclusive

Syntax for Propositions

- Boolean random variables
 e.g., Cavity (do I have a cavity?)
 Cavity = true is a proposition, also written cavity
- Discrete random variables (finite or infinite)
 e.g., Weather is one of < sunny, rain, cloudy, snow > Weather = rain is a proposition
 Values must be exhaustive and mutually exclusive
- ► Continuous random variables (bounded or unbounded) e.g., Temp = 21.6; also allow, e.g., Temp < 22.0.

Prior Probability and (Joint) Probability Distribution

▶ Prior or unconditional probabilities of propositions, e.g. P(Cavity = true) = 0.1 and P(Weather = sunny) = 0.72 correspond to belief prior to arrival of any (new) evidence

¹Every question about a domain can be answered by the joint distribution because every event is a sum of sample points

Prior Probability and (Joint) Probability Distribution

- ▶ **Prior** or **unconditional probabilities** of propositions, e.g. P(Cavity = true) = 0.1 and P(Weather = sunny) = 0.72 correspond to belief prior to arrival of any (new) evidence
- ▶ Probability distribution gives values for all possible assignments: P(Weather) =< 0.72, 0.1, 0.08, 0.1 > (normalised, i.e. sums to 1)

¹Every question about a domain can be answered by the joint distribution because every event is a sum of sample points

Prior Probability and (Joint) Probability Distribution

- ▶ Prior or unconditional probabilities of propositions, e.g. P(Cavity = true) = 0.1 and P(Weather = sunny) = 0.72 correspond to belief prior to arrival of any (new) evidence
- ▶ Probability distribution gives values for all possible assignments: P(Weather) =< 0.72, 0.1, 0.08, 0.1 > (normalised, i.e. sums to 1)
- ▶ **Joint probability distribution**¹ gives the probability of every atomic event on a set of random variables (i.e. every sample point), e.g. $P(Weather, Cavity) = a \ 4 \times 2$ matrix of values:

Weather =		-	-	-
Cavity = true	0.144	0.02	0.016	0.02
Cavity = false	0.576	0.08	0.064	0.08

¹Every question about a domain can be answered by the joint distribution because every event is a sum of sample points

Conditional Probability (1/3)

► Conditional or posterior probabilities e.g., P(cavity|toothache) = 0.8, i.e. given that toothache is all I know ... NOT "if toothache then 80% chance of cavity"

Conditional Probability (1/3)

- ▶ Conditional or posterior probabilities e.g., P(cavity|toothache) = 0.8, i.e. given that toothache is all I know ... NOT "if toothache then 80% chance of cavity"

Conditional Probability (1/3)

- ▶ Conditional or posterior probabilities e.g., P(cavity|toothache) = 0.8, i.e. given that toothache is all I know ... NOT "if toothache then 80% chance of cavity"
- New evidence may be irrelevant, allowing simplification, e.g. P(cavity|toothache, Weather) = P(cavity|toothache) = 0.8

Conditional Probability (2/3)

▶ Conditional probability: $P(a|b) = \frac{P(a \land b)}{P(b)}$ if $P(b) \neq 0$

Conditional Probability (2/3)

- ► Conditional probability: $P(a|b) = \frac{P(a \land b)}{P(b)}$ if $P(b) \neq 0$
- ► The **product rule** gives an alternative formulation: $P(a \land b) = P(a|b)P(b) = P(b|a)P(a)$

Conditional Probability (2/3)

- ► Conditional probability: $P(a|b) = \frac{P(a \land b)}{P(b)}$ if $P(b) \neq 0$
- ► The **product rule** gives an alternative formulation: $P(a \land b) = P(a|b)P(b) = P(b|a)P(a)$
- A general version holds for whole distributions, e.g.,
 P(Weather, Cavity) = P(Weather | Cavity)P(Cavity)
 (View as a 4 × 2 set of equations, not matrix multiplication)

```
\begin{split} &P(W=sunny \land C=true) = P(W=sunny | C=true) \ P(C=true) \\ &P(W=rain \land C=true) = P(W=rain | C=true) \ P(C=true) \\ &P(W=cloudy \land C=true) = P(W=cloudy | C=true) \ P(C=true) \\ &P(W=snow \land C=true) = P(W=snow | C=true) \ P(C=true) \\ &P(W=sunny \land C=false) = P(W=sunny | C=false) \ P(C=false) \\ &P(W=rain \land C=false) = P(W=rain | C=false) \ P(C=false) \\ &P(W=cloudy \land C=false) = P(W=cloudy | C=false) \ P(C=false) \\ &P(W=snow \land C=false) = P(W=snow | C=false) \ P(C=false) \ . \end{split}
```

Conditional Probability (3/3)

The chain rule is derived by the successive application of the product rule:

```
► P(X_1, X_2) = P(X_2|X_1)P(X_1)

► P(X_1, X_2, X_3) = P(X_3|X_2, X_1)P(X_2, X_1)

► = P(X_3|X_2, X_1)P(X_2|X_1)P(X_1)

► P(X_1, X_2, X_3, X_4) = ?

► ...

► P(X_1, \dots, X_n) = P(X_1)P(X_2|X_1)P(X_3|X_2, X_1) \dots

► P(X_1, \dots, X_n) = \prod_{i=1}^n P(X_i|X_{i-1}, \dots, X_1)
```

Conditional Probability (3/3)

The chain rule is derived by the successive application of the product rule:

►
$$P(X_1, X_2) = P(X_2|X_1)P(X_1)$$

► $P(X_1, X_2, X_3) = P(X_3|X_2, X_1)P(X_2, X_1)$
► $P(X_1, X_2, X_3, X_4) = ?$
► ...
► $P(X_1, ..., X_n) = P(X_1)P(X_2|X_1)P(X_3|X_2, X_1)...$
► $P(X_1, ..., X_n) = \prod_{i=1}^n P(X_i|X_{i-1}, ..., X_1)$

▶ Bayes Rule:
$$P(A|B) = \frac{P(B|A)P(A)}{P(B)}$$
$$= \frac{P(B|A)P(A)}{\sum_{i}^{n} P(B|A_{i})P(A_{i})}$$

▶ Marginalisation is the process of summing up the probabilities of the other variables—i.e. taking them out of the equation.

- Marginalisation is the process of summing up the probabilities of the other variables—i.e. taking them out of the equation.
- ▶ General rule for any set of variables Y and Z: $P(Y) = \sum_{z in Z} P(Y, z)$

- Marginalisation is the process of summing up the probabilities of the other variables—i.e. taking them out of the equation.
- ▶ General rule for any set of variables Y and Z: $P(Y) = \sum_{z in Z} P(Y, z)$
- ▶ For example: $P(Cavity) = \sum_{z \in \{Catch, Toothache\}} P(Cavity, z)$

- Marginalisation is the process of summing up the probabilities of the other variables—i.e. taking them out of the equation.
- ▶ General rule for any set of variables Y and Z: $P(Y) = \sum_{z in Z} P(Y, z)$
- ▶ For example: $P(Cavity) = \sum_{z \in \{Catch, Toothache\}} P(Cavity, z)$
- Consider the following joint distribution:

	toothache		¬ toothache	
	catch	¬ catch	catch	¬ catch
cavity	.108	.012	.072	.008
¬ cavity	.016	.064	.144	.576

Inference by Enumeration (1/3)

Start with the joint distribution:

	toothache		¬ toothache	
	catch	¬ catch	catch	¬ catch
cavity	.108	.012	.072	.008
¬ cavity	.016	.064	.144	.576

For any proposition ϕ , sum the atomic events where it is true: $P(\phi) = \sum_{\omega:\omega\models\phi} P(\omega)$

$$P(toothache) = 0.108 + 0.012 + 0.016 + 0.064 = 0.2$$

Inference by Enumeration (2/3)

Start with the joint distribution:

	toothache		¬ toothache	
	catch	¬ catch	catch	¬ catch
cavity	.108	.012	.072	.008
¬ cavity	.016	.064	.144	.576

For any proposition ϕ , sum the atomic events where it is true: $P(\phi) = \sum_{\omega:\omega\models\phi} P(\omega)$

$$P(cavity \lor toothache) = 0.108 + 0.012 + 0.072 + 0.008 + 0.016 + 0.064 = 0.28$$

Inference by Enumeration (3/3)

Start with the joint distribution:

	toothache		¬ toothache	
	catch	¬ catch	catch	¬ catch
cavity	.108	.012	.072	.008
¬ cavity	.016	.064	.144	.576

We can also compute conditional probabilities:

$$P(\neg cavity | toothache) = \frac{P(\neg cavity \land toothache)}{P(toothache)}$$
$$= \frac{0.016 + 0.064}{0.108 + 0.012 + 0.016 + 0.064} = 0.4$$

Normalisation

	toothache		¬ toothache	
	catch	¬ catch	catch	¬ catch
cavity	.108	.012	.072	.008
¬ cavity	.016	.064	.144	.576

The denominator can be viewed as a normalization constant α

$$\begin{aligned} & \mathbf{P}(\textit{Cavity} | \textit{toothache}) = \alpha \ \mathbf{P}(\textit{Cavity}, \textit{toothache}) \\ &= \alpha \left[\mathbf{P}(\textit{Cavity}, \textit{toothache}, \textit{catch}) + \mathbf{P}(\textit{Cavity}, \textit{toothache}, \neg \textit{catch}) \right] \\ &= \alpha \left[< 0.108, 0.016 > + < 0.012, 0.064 > \right] \\ &= \alpha < 0.12, 0.08 > = < 0.6, 0.4 > \end{aligned}$$

General idea: compute distribution on query variable by fixing evidence variables and summing over hidden variables

1.5

Keywords

- Probability Distribution
- Joint Probability
- Conditional Probability
- Prior Probability
- Posterior Probability
- Product Rule
- Sum Rule
- Chain Rule
- Marginalisation
- Normalisation
- Inference
- Bayes Rule
- Probabilistic Model

Next

Workshop:

- Excercises about quantifying uncertainty, Q&A
- Wednesday from 10:30-12hrs, room=INB1301

Readings:

- Russel, S.& Norvig, P. (2013). "Artificial Intelligence: A Modern Approach", chapter13 (main reading)
- Bishop, C. "Model-Based Machine Learning", chapter1 (optional reading)