732A96 Advanced Machine Learning

Graphical Models and Hidden Markov Models

Jose M. Peña
IDA, Linköping University, Sweden

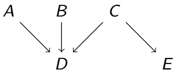
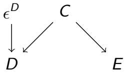
Lecture 1: Causal Models, Bayesian Networks and Markov Networks

Contents

Literature

- Main source
  - Bishop, C. M. *Pattern Recognition and Machine Learning*. Springer, 2006.
- Additional source
  - Koski, T. J. T. and Noble, J. M. A Review of Bayesian Networks and Structure Learning. *Mathematica Applicanda* 40, 51-103, 2012.

Causal Models: Qualitative

Microscopic DAG	Macroscopic DAG	Macroscopic Violates assumption
		

- At the microscopic level, every system is a causal system, **assuming** Reichenbach's principle of common cause: "No correlation without causation".
- Then, at the microscopic level, every system can be represented by a causal model.
- The structure of the causal model can be represented as a **directed and acyclic graph (DAG)**.
- At the macroscopic level, every system can be represented by a causal model **if no unmodeled variable** is cause of two or more modeled variables. The unmodeled causes of a variable X are aggregated into an error variable ϵ^X.

Causal Models: Quantitative

<table>
<tr><th>Microscopic
DAG
Functional</th><th>Macroscopic
DAG
Functional</th><th>Macroscopic
DAG
Probabilistic</th></tr>
<tr>
<td>

$$\begin{tikzcd} A \arrow[dr] & B \arrow[d] & C \arrow[dl] \arrow[dr] & \\ & D = f(A,B,C) & & E = f(C) \end{tikzcd}$$

</td>
<td>

$$\begin{tikzcd} \epsilon^D \arrow[d] & C \arrow[dl] \arrow[dr] & \\ D = f(C,\epsilon^D) & & E = f(C) \end{tikzcd}$$

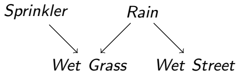
</td>
<td>

$$\begin{tikzcd} & C \arrow[dl] \arrow[dr] & \\ D \sim q(D|C) & & E \sim q(E|C) \end{tikzcd}$$

</td>
</tr>
</table>

- **Assuming** Laplace's demon, every variable is a deterministic function of its causes at the microscopic level.
- Then, every variable is a probabilistic function of its modeled causes at the macroscopic level.
- Both Reichenbach's principle of common cause and Laplace's demon have been disproven. Human reasoning seem to comply with both of them, though.
- Then, probabilistic DAGs may not be ontological but epistemological models. They also help to identify key questions about reasoning.

Bayesian Networks: Definition

DAG	Parameter values for the conditional probility distributions
	$q(S) = (0.3, 0.7)$ $q(R) = (0.5, 0.5)$ $q(WG \mid r_0, s_0) = (0.1, 0.9)$ $q(WG \mid r_0, s_1) = (0.7, 0.3)$ $q(WG \mid r_1, s_0) = (0.8, 0.2)$ $q(WG \mid r_1, s_1) = (0.9, 0.1)$ $q(WS \mid r_0) = (0.1, 0.9)$ $q(WS \mid r_1) = (0.7, 0.3)$ $p(S, R, WG, WS) = q(S)q(R)q(WG \mid S, R)q(WS \mid R)$

- A **Bayesian network (BN)** over a finite set of **discrete** random variables $X = X_{1:n} = \{X_1, \ldots, X_n\}$ consists of
  - a DAG G whose nodes are the elements in X, and
  - parameter values θ_G specifying conditional probability distributions $q(X_i \mid pa_G(X_i))$.
- The BN represents a causal model of the system.
- The BN also represents a probabilistic model of the system, namely $p(X) = \prod_i q(X_i \mid pa_G(X_i))$.

Bayesian Networks: Definition

- We now show that $p(X) = \prod_i q(X_i | pa_G(X_i))$ is a probability distribution.
- Clearly, $0 \leq \prod_i q(X_i | pa_G(X_i)) \leq 1$.
- Assume without loss of generality that $pa_G(X_i) \subseteq X_{1:i-1}$ for all i. Then

$$\sum_x \prod_i q(x_i | pa_G(X_i)) = \sum_{x_1} [q(x_1) \dots \sum_{x_{n-1}} [q(x_{n-1} | pa_G(X_{n-1})) \sum_{x_n} q(x_n | pa_G(X_n))] \dots] = 1$$

- Moreover, $p(X_i | pa_G(X_i)) = q(X_i | pa_G(X_i))$. To see it, note that

$$p(X_i | pa_G(X_i)) = \frac{p(X_i, pa_G(X_i))}{p(pa_G(X_i))} = \frac{\sum_{X \setminus \{X_i, pa_G(X_i)\}} \prod_i q(X_i | pa_G(X_i))}{\sum_{X \setminus pa_G(X_i)} \prod_i q(X_i | pa_G(X_i))} = q(X_i | pa_G(X_i))$$

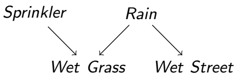
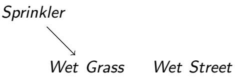
Bayesian Networks: Separation

- We now show that many of the independencies in p can be read off G without numerical calculations.
- Let ρ be a path between two nodes α and β in G.
- A node B in ρ is a **collider** when $A \rightarrow B \leftarrow C$ is a subpath of ρ.
- Moreover, ρ is Z-open with $Z \subseteq X \setminus \{\alpha, \beta\}$ when
  - no non-collider in ρ is in Z, and
  - every collider in ρ is in Z or has a descendant in Z.
- Let U, V and Z be three disjoint subsets of X. Then, U and V are **separated** given Z in G (i.e. $U \perp_G V|Z$) when there is no Z-open path in G between a node in U and a node in V.
- The separation criterion is **sound**, i.e. if $U \perp_G V|Z$ then $U \perp_p V|Z$.
- Moreover, it is also **complete**, i.e. p may be such that $U \perp_G V|Z$ if and only if $U \perp_p V|Z$.
- Moreover, p factorizes as $p(X) = \prod_i q(X_i|pa_G(X_i))$ if and only if it satisfies all the independencies identified by the separation criterion.

Bayesian Networks: Separation

- **Exercise**. Prove that $A \perp_p B | C$ for the DAGs $A \to C \to B$, $A \leftarrow C \to B$ and $A \leftarrow C \leftarrow B$, i.e. prove that $p(A, B|C) = p(A|C)p(B|C)$.
- **Exercise**. Prove that $A \perp_p B | \varnothing$ for the DAG $A \to C \leftarrow B$, i.e. prove that $p(A, B) = p(A)p(B)$.
- **Exercise**. Prove that $A \perp_p B | C, D$ for the DAG $A \to C \to D \to B$.
- **Exercise**. Prove that $A \perp_p B | C, D$ for the DAG $A \to C \to D \leftarrow B$.
- **Exercise**. Find the minimal set of nodes that separates a given node from the rest. This set is called the Markov blanket of the given node.

Bayesian Networks: Causal Reasoning

Original	After $do(r_1)$
	
$q(S) = (0.3, 0.7)$ $q(R) = (0.5, 0.5)$ $q(WG \mid r_0, s_0) = (0.1, 0.9)$ $q(WG \mid r_0, s_1) = (0.7, 0.3)$ $q(WG \mid r_1, s_0) = (0.8, 0.2)$ $q(WG \mid r_1, s_1) = (0.9, 0.1)$ $q(WS \mid r_0) = (0.1, 0.9)$ $q(WS \mid r_1) = (0.7, 0.3)$	$q(S) = (0.3, 0.7)$ $q(WG \mid s_0) = (0.8, 0.2)$ $q(WG \mid s_1) = (0.9, 0.1)$ $q(WS) = (0.7, 0.3)$
$p(S, R, WG, WS) = q(S)q(R)q(WG \mid S, R)q(WS \mid R)$	$p(S, WG, WS) = q(S)q(WG \mid S)q(WS)$

- What would be the state of the system if a random variable X_j is forced to take the state x_j, i.e. $p(X \setminus X_j \mid do(x_j))$?
  - Remove X_j and all the edges from and to X_j from G.
  - Remove $q(X_j \mid pa_G(X_j))$.
  - If $X_j \in pa_G(X_i)$, then replace $q(X_i \mid pa_G(X_i))$ with $q(X_i \mid pa_G(X_i) \setminus X_j, x_j)$
  - Set $p(X \setminus X_j \mid do(x_j)) = \prod_i q(X_i \mid pa_G(X_i))$.
- So, the result of $do(x)$ on a BN **is a BN**.

Bayesian Networks: Probabilistic Reasoning

- What is the state of the system if a random variable X_i is observed to be in the state x_i, i.e. $p(X \setminus X_i | x_i)$?
  - $p(X \setminus X_i | x_i) = \frac{p(X \setminus X_i, x_i)}{p(x_i)} = \frac{p(X \setminus X_i, x_i)}{\sum_{X \setminus X_i} p(X \setminus X_i, x_i)}$
  - $p(R, WG, WS | s) = \frac{q(s)q(R)q(WG|s,R)q(WS|R)}{\sum_{r,wg,ws} q(s)q(r)q(wg|s,r)q(ws|r)}$
    $= \frac{q(s)q(R)q(WG|s,R)q(WS|R)}{q(s)\sum_r [q(r)\sum_{wg}[q(wg|s,r)\sum_{ws} q(ws|r)]]}$
- What is the state of a random variable Y if a random variable X_i is observed to be in the state x_i, i.e. $p(Y|x_i)$?
  - $p(Y|x_i) = \frac{p(Y, x_i)}{p(x_i)} = \frac{\sum_{X \setminus \{X_i, Y\}} p(X \setminus X_i, x_i)}{\sum_{X \setminus X_i} p(X \setminus X_i, x_i)}$
  - $p(WS|s) = \frac{\sum_{r,wg} q(s)q(r)q(wg|s,r)q(WS|r)}{\sum_{r,wg,ws} q(s)q(r)q(wg|s,r)q(ws|r)}$
    $= \frac{q(s)\sum_r [q(r)q(WS|r)\sum_{wg} q(wg|s,r)]}{q(s)\sum_r [q(r)\sum_{wg}[q(wg|s,r)\sum_{ws} q(ws|r)]]}$
- What is the state of a random variable Y if a random variable X_i is observed to be in the state x_i, after forcing a random variable X_j to take the state x_j, i.e. $p(Y|x_i, do(x_j))$?
- Answering questions like the one above can be computationally hard.
- A BN is an efficient formalism to compute a posterior probability distribution from a prior probability distribution in the light of observations, hence the name.

Markov Networks: Definition

UG	Potentials assuming binary random variables
$\begin{tikzcd} A \arrow[r, dash] \arrow[d, dash] & B \arrow[d, dash] \arrow[dl, dash] \\ C \arrow[r, dash] & D \end{tikzcd}$	$\varphi(A,B,C) = (1,1,1,1,1,1,1,1)$ $\varphi(B,C,D) = (2,2,2,2,2,2,2,2)$ $p(A,B,C,D) = \varphi(A,B,C)\varphi(B,C,D)/Z$ with $Z = \sum_{a,b,c,d} \varphi(a,b,c)\varphi(b,c,d)$

- A **Markov network (MN)** over X consists of
  - an undirected graph (UG) G whose nodes are the elements in X, and
  - a set of non-negative functions $\varphi(K)$ over the cliques $Cl(G)$ of G.
- A clique is a maximal complete set of nodes. The functions are called potentials.
- The MN represents a probabilistic model of the system, namely

$$p(X) = \frac{1}{Z} \prod_{K \in Cl(G)} \varphi(K)$$

where Z is a normalization constant, i.e.

$$Z = \sum_{x} \prod_{K \in Cl(G)} \varphi(k)$$

- Clearly, $p(X)$ is a probability distribution.

Markov Networks: Separation

- We now show that many of the independencies in p can be read off G without numerical calculations.
- A path ρ between two nodes α and β in G is Z-open with $Z \subseteq X \setminus \{\alpha, \beta\}$ when no node in ρ is in Z.
- Let U, V and Z be three disjoint subsets of X. Then, U and V are **separated** given Z in G (i.e. $U \perp_G V | Z$) when there is no Z-open path in G between a node in U and a node in V.
- The separation criterion is **sound**, i.e. if $U \perp_G V | Z$ then $U \perp_p V | Z$.
- Moreover, it is also **complete**, i.e. p may be such that $U \perp_G V | Z$ if and only if $U \perp_p V | Z$.
- Moreover, p factorizes as $p(X) = \frac{1}{Z} \prod_{K \in Cl(G)} \varphi(K)$ if and only if it satisfies all the independencies identified by the separation criterion.

Markov Networks: Separation

- **Exercise**. Prove that $A \perp_p B | C$ for the UG $A - C - B$, i.e. prove that $p(A, B|C) = f(A, C)g(B, C)$ for some functions f and g.
- **Exercise**. Find the minimal set of nodes that separates a given node from the rest. This set is called the Markov blanket of the given node.

Markov Networks: Factor Graphs

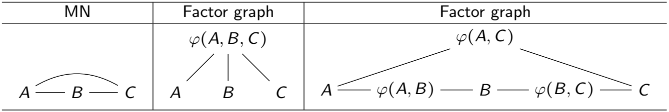
- What if $\varphi(C_i) = \prod_j \phi(C_i^j)$ with $C_i^j \subseteq C_i$?
- A MN may obscure the structure of the potentials. Solution: Factor graphs.
- A factor graph over X consists of an UG G with two types of nodes: The elements in X and a set of potentials $\varphi(K)$ over subsets of X. All the edges in G are between a potential and the elements of X that are in its domain.
- The factor graph represents a probabilistic model of the system, namely

$$p(X) = \frac{1}{Z} \prod_K \varphi(K)$$

where Z is a normalization constant, i.e.

$$Z = \sum_x \prod_K \varphi(k)$$

- Factor graphs: Finer-grained parameterization of MNs.



Markov Networks: Probabilistic Reasoning

- In the first example above, what is the state of a random variable A if a random variable B is observed to be in the state b ?

$$p(A|b) = \frac{\sum_{c,d} \varphi(A,b,c)\varphi(b,c,d)}{\sum_{a,c,d} \varphi(a,b,c)\varphi(b,c,d)} = \frac{\sum_{c}[\varphi(A,b,c)\sum_{d}\varphi(b,C,d)]}{\sum_{a,c}[\varphi(a,b,c)\sum_{d}\varphi(b,c,d)]}$$

- Answering questions like the one above can be computationally hard.
- A MN is an efficient formalism to answer such questions.

Intersection of Bayesian Networks and Markov Networks

- An **unshielded collider** in a DAG is a subgraph of the form $A \to C \leftarrow B$ such that A and B are not adjacent in the DAG.
- An UG is **triangulated** if every cycle in it contains a chord, i.e. an edge between two non-consecutive nodes in the cycle.
- Given a DAG G, there is an UG H such that $I(G) = I(H)$ if and only if G has no unshielded colliders.
- Given an UG G, there is an DAG H such that $I(G) = I(H)$ if and only if G is triangulated.