ENM 531: Data-driven Modeling and Probabilistic Scientific Computing

Lecture #3: Primer on Probability and Statistics

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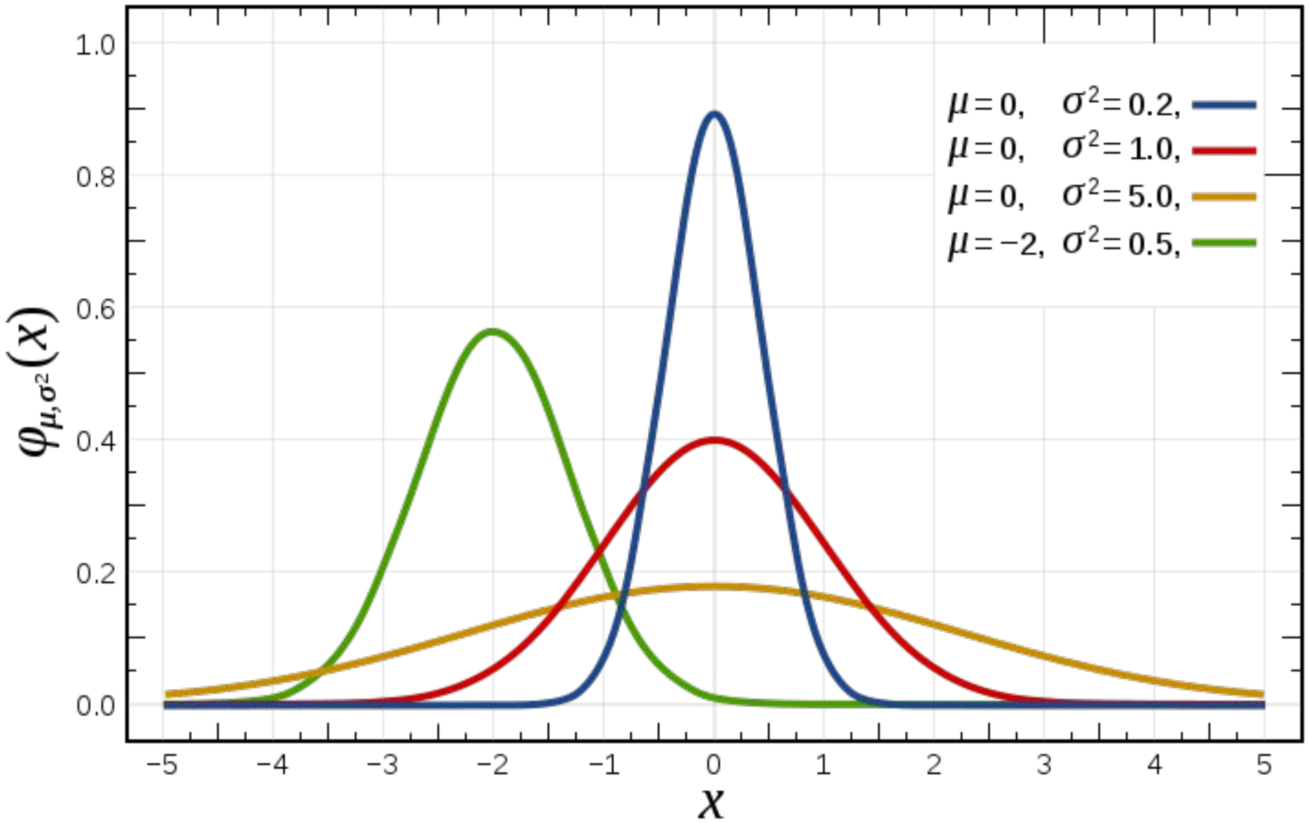
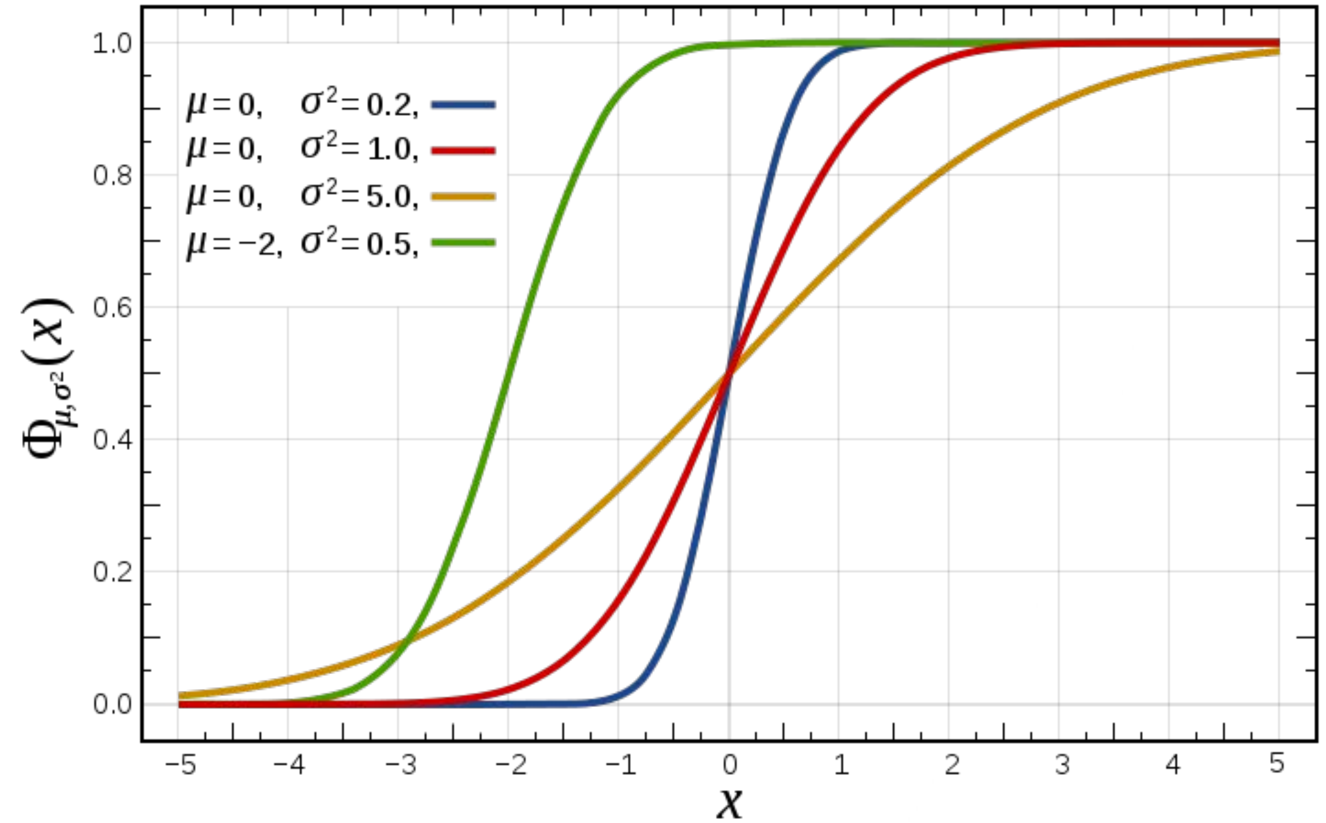
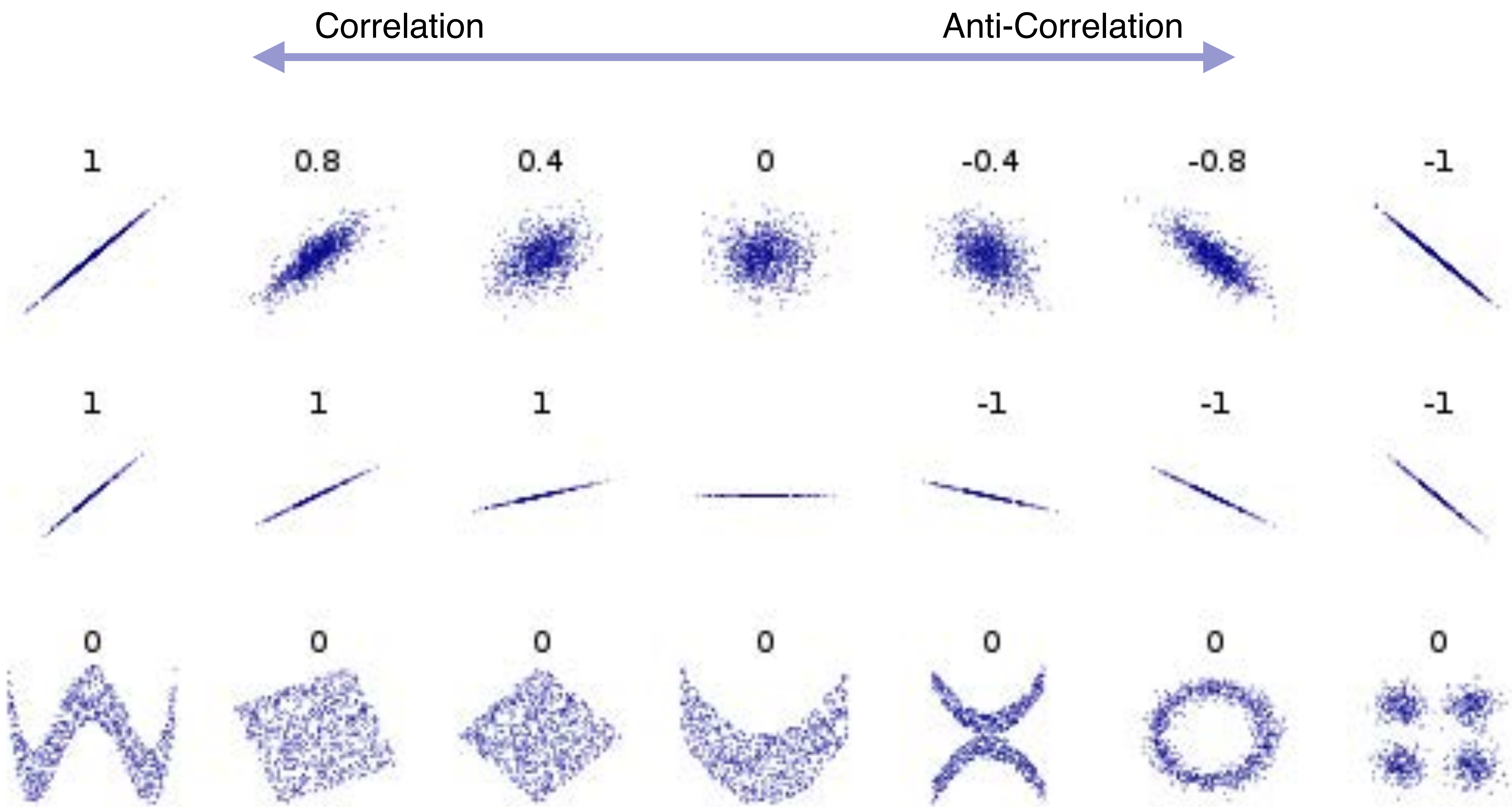
The Gaussian distribution



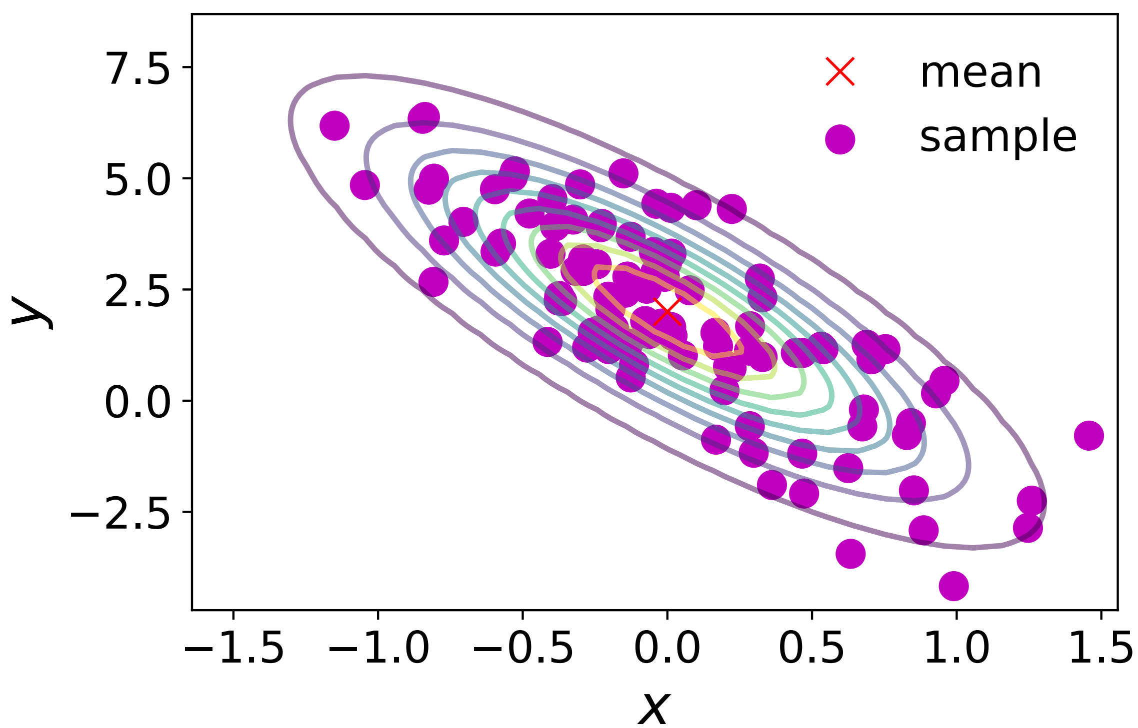


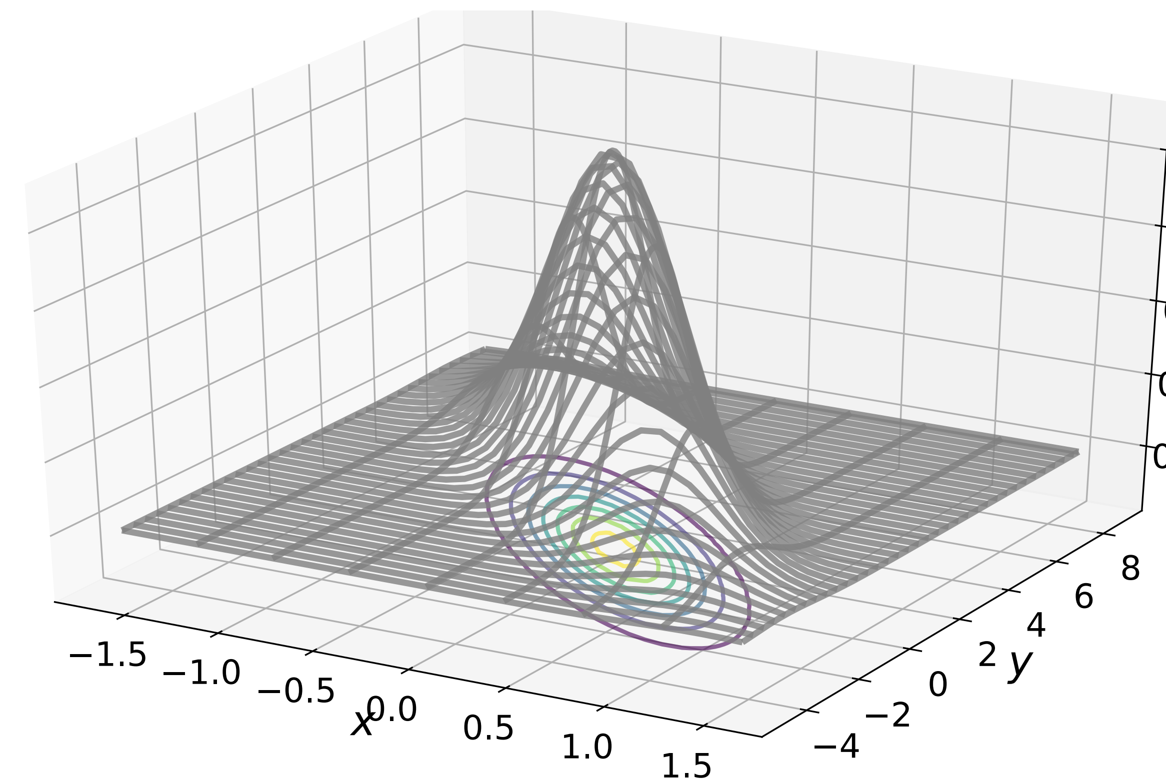
Notation	$\mathcal{N}(\mu,\, \sigma^2)$
Parameters	$\mu \in \mathbb{R}$ = mean (location) $\sigma^2 > 0$ = variance (squared scale)
Support	$x \in \mathbb{R}$
PDF	$\frac{1}{\sqrt{2\pi\sigma^2}}\, e^{-\frac{(x-\mu)^2}{2\sigma^2}}$
CDF	$\frac{1}{2}\left[1+\operatorname{erf}\left(\frac{x-\mu}{\sigma\sqrt{2}}\right)\right]$
Quantile	$\mu+\sigma\sqrt{2}\operatorname{erf}^{-1}(2F-1)$
Mean	μ
Median	μ
Mode	μ
Variance	σ^2

Correlation and linear dependence



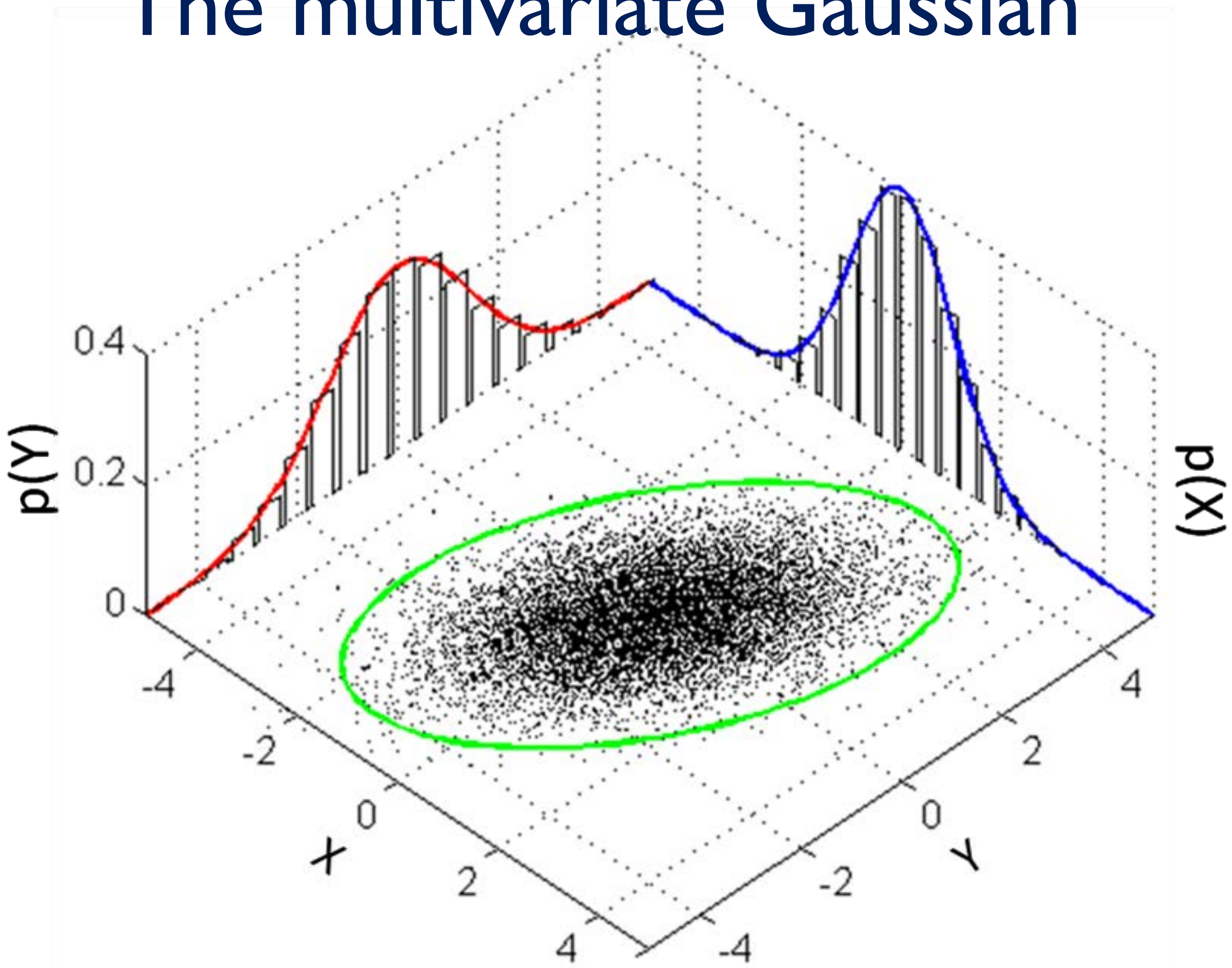
The multivariate Gaussian





$$p(\boldsymbol{x} \mid \boldsymbol{\mu}, \boldsymbol{\Sigma}) = (2\pi)^{-\frac{D}{2}} |\boldsymbol{\Sigma}|^{-\frac{1}{2}} \exp\big(-\tfrac{1}{2}(\boldsymbol{x}-\boldsymbol{\mu})^\top \boldsymbol{\Sigma}^{-1}(\boldsymbol{x}-\boldsymbol{\mu})\big)$$

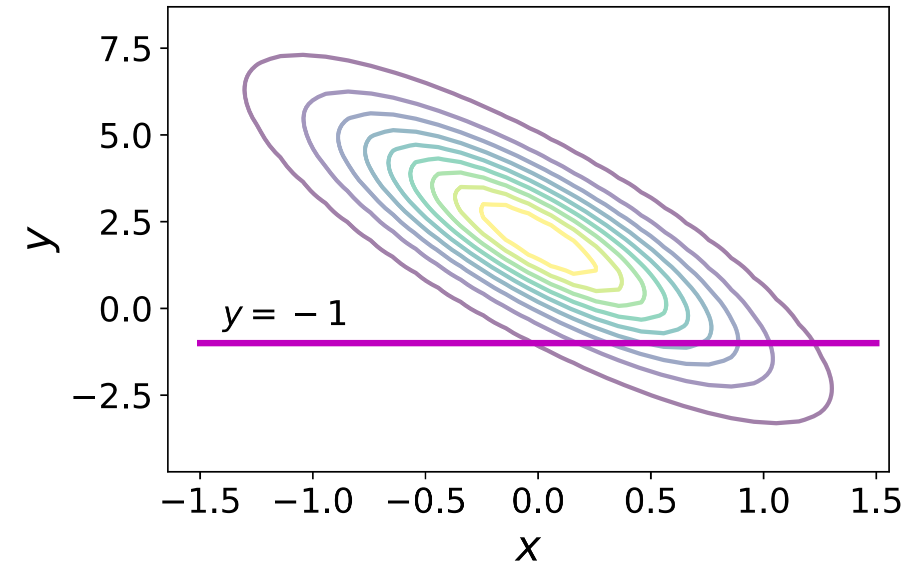
The multivariate Gaussian



Notation	$\mathcal{N}(\boldsymbol{\mu},\, \boldsymbol{\Sigma})$
Parameters	$\boldsymbol{\mu} \in \mathbf{R}^k$ — location $\boldsymbol{\Sigma} \in \mathbf{R}^{k \times k}$ — covariance (positive semi-definite matrix)
Support	$\boldsymbol{x} \in \boldsymbol{\mu} + \mathrm{span}(\boldsymbol{\Sigma}) \subseteq \mathbf{R}^k$
PDF	$\det(2\pi\boldsymbol{\Sigma})^{-\frac{1}{2}}\, e^{-\frac{1}{2}(\mathbf{x}-\boldsymbol{\mu})'\boldsymbol{\Sigma}^{-1}(\mathbf{x}-\boldsymbol{\mu})}$, exists only when $\boldsymbol{\Sigma}$ is positive-definite
Mean	$\boldsymbol{\mu}$
Mode	$\boldsymbol{\mu}$
Variance	$\boldsymbol{\Sigma}$

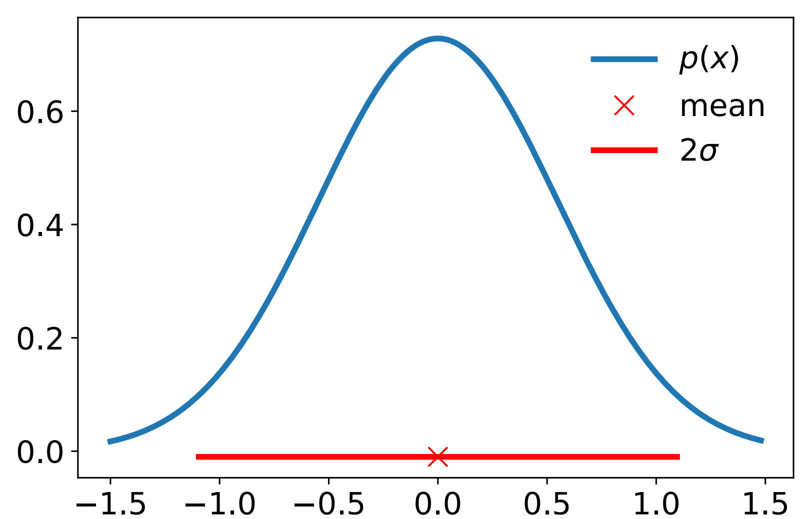
Marginals and conditionals of a Gaussian

$$p(\boldsymbol{x}, \boldsymbol{y}) = \mathcal{N}\left(\begin{bmatrix}\boldsymbol{\mu}_x \\ \boldsymbol{\mu}_y\end{bmatrix}, \begin{bmatrix}\boldsymbol{\Sigma}_{xx} & \boldsymbol{\Sigma}_{xy} \\ \boldsymbol{\Sigma}_{yx} & \boldsymbol{\Sigma}_{yy}\end{bmatrix}\right)$$



Marginal distribution

$$p(\boldsymbol{x}) = \int p(\boldsymbol{x}, \boldsymbol{y}) d\boldsymbol{y} = \mathcal{N}(\boldsymbol{x} \,|\, \boldsymbol{\mu}_x, \boldsymbol{\Sigma}_{xx})$$

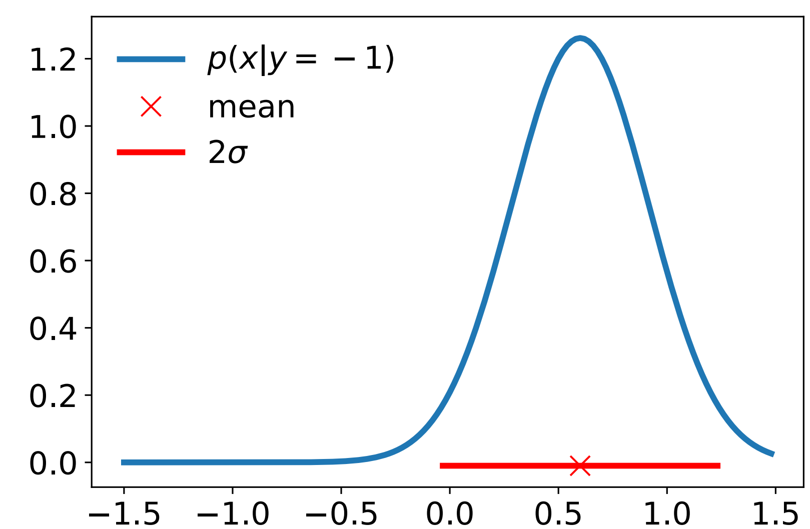


Conditional distribution

$$p(\boldsymbol{x} \,|\, \boldsymbol{y}) = \mathcal{N}(\boldsymbol{\mu}_{x\,|\,y}, \boldsymbol{\Sigma}_{x\,|\,y})$$

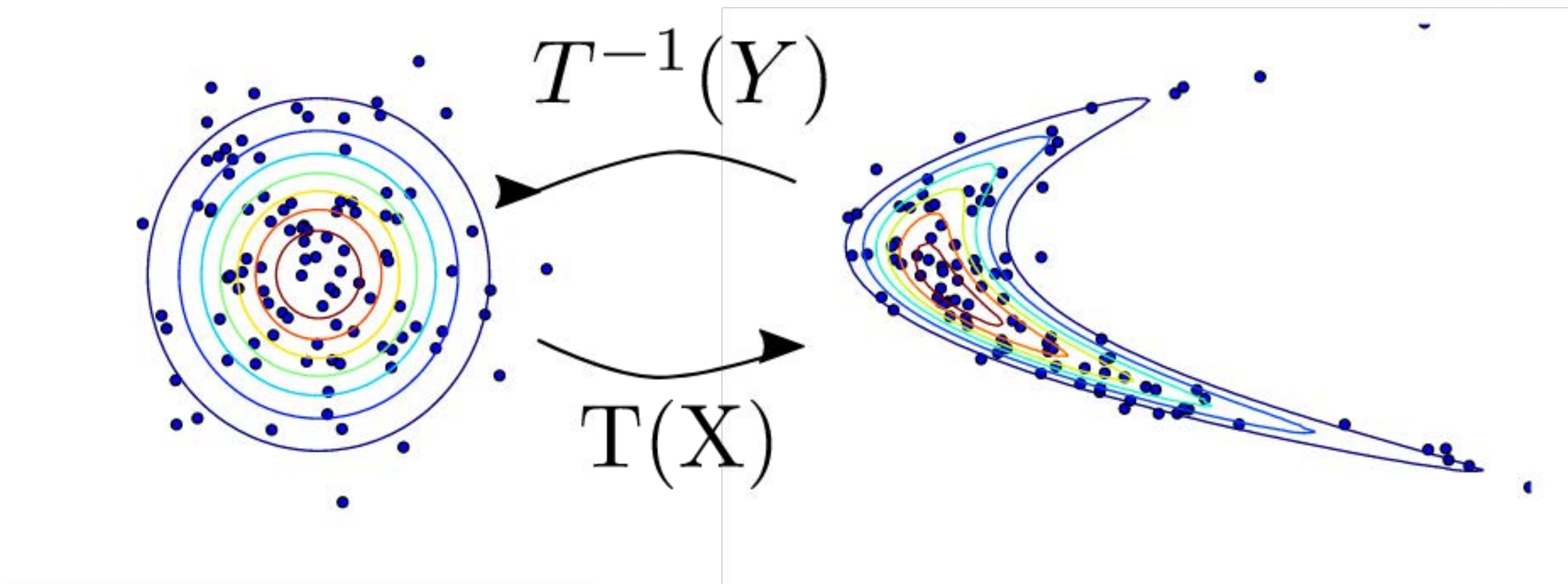
$$\boldsymbol{\mu}_{x\,|\,y} = \boldsymbol{\mu}_x + \boldsymbol{\Sigma}_{xy}\boldsymbol{\Sigma}_{yy}^{-1}(\boldsymbol{y} - \boldsymbol{\mu}_y)$$

$$\boldsymbol{\Sigma}_{x\,|\,y} = \boldsymbol{\Sigma}_{xx} - \boldsymbol{\Sigma}_{xy}\boldsymbol{\Sigma}_{yy}^{-1}\boldsymbol{\Sigma}_{yx} \,.$$



These are unique properties that make the Gaussian distribution very simple and attractive to compute with! It is essentially our main building block for computing under uncertainty.

Transformations



Maximum likelihood estimation

$$\theta_{\text{MLE}} = \arg\max_{\theta \in \Theta} p(\mathcal{D}|\theta)$$