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Abstract

The Proposed S Distance

We consider the one dimensional case as a start, where x_r are real samples sampled from distribution $\mathbb{P}_r$, and x_g are generated samples sampled from distribution $\mathbb{P}_g$,

$$x_r \sim \mathbb{P}_r \tag{1}$$

$$x_g \sim \mathbb{P}_g \tag{2}$$

Note that both x_r and x_g are restricted between $[0, 1]$.

Following is the proposed S distance,

$$S(\mathbb{P}_r, \mathbb{P}_g) = \mathbb{E}_{x_g \sim \mathbb{P}_g}\{|\int_{x_g}^{1} \mathbb{P}_r(x)dx - \int_{x_g}^{1} \mathbb{P}_g(x)dx|\} \tag{3}$$

while the Wasserstein distance is defined to be,

$$W(\mathbb{P}_r, \mathbb{P}_g) = \sup_{\|f\|_L \leq 1} \{\mathbb{E}_{x_r \sim \mathbb{P}_r}[f(x_r)] - \mathbb{E}_{x_g \sim \mathbb{P}_g}[f(x_g)]\} \tag{4}$$

Apparently, both S and W distance will be minimized if the $\mathbb{P}_r$ and $\mathbb{P}_g$ are identical. To take a deeper insight of the advantage of the proposed S distance, we consider the representation of these two distance at a sample x_g. This is crucial, since when updating *Generator G*, it only observe at a specific x_g instead of having a whole sight of the distributions $\mathbb{P}_r$ and $\mathbb{P}_g$. The S at x is,

$$S_{\mathbb{P}_r,\mathbb{P}_g}(x_g) = |\int_{x_g}^{1} \mathbb{P}_r(x)dx - \int_{x_g}^{1} \mathbb{P}_g(x)dx| \tag{5}$$

while the W at x is,

$$W_{\mathbb{P}_r,\mathbb{P}_g}(x_g) = f(x) \approx \mathbb{P}_r(x) - \mathbb{P}_g(x) \tag{6}$$

We can see that $S_{\mathbb{P}_r,\mathbb{P}_g}(x_g)$ consider how unbalance are the two distributions in a whole sight, while the $W_{\mathbb{P}_r,\mathbb{P}_g}(x_g)$ considers the unbalance of the two probabilities only at this point.

GAN Based on S Distance

For every x_r, x_g pair, we sample x_τ between x_r and x_g,

$$x_\tau = \tau x_r + (1 - \tau)x_g \tag{7}$$

where

$$\tau \sim U[0, 1] \tag{8}$$

Consider our problem on a discrete space with interval of ε, we give every notation of x a check mark, i.e., $\check{x}$, to mark that they are discrete value under interval ε. Later on we will derive its limitation to have a general conclusion on the continuous space. Now consider a event denoted by: $\check{x}_\tau \overset{t}{=} \check{x}_n$, which means,

- Sample $\check{x}_\tau$ for t times, $\check{x}_n$ got sampled at least for one time.

Apparently, we have,

$$d = |\check{x}_r - \check{x}_g| \tag{9}$$

$$P(\check{x}_\tau \overset{1}{=} \check{x}_n | \check{x}_r, \check{x}_g) = \begin{cases} \frac{1}{d/\varepsilon} & \check{x}_r < \check{x}_n < \check{x}_g, \check{x}_g < \check{x}_n < \check{x}_r \\ 0 & \text{else} \end{cases} \tag{10}$$

If we sample $\check{x}_\tau$ for t times, where

$$t = d/\delta \tag{11}$$

Here, δ is also approaching to zero. We assume it is in the same order as ε approaching zero[1]. Then, we,

$$\begin{aligned} & P(x_\tau \overset{t}{=} x_n | x_r, x_g) \\ = \ & 1 - (1 - P(\check{x}_\tau \overset{1}{=} \check{x}_n | \check{x}_r, \check{x}_g))^t \\ = \ & \begin{cases} 1 - (1 - \frac{1}{d/\varepsilon})^{d/\delta} & \check{x}_r < \check{x}_n < \check{x}_g, \check{x}_g < \check{x}_n < \check{x}_r \\ 0 & \text{else} \end{cases} \end{aligned}$$

[1] In practice, ε may approach zero in a much more higher order than δ approaching zero, i.e., $\varepsilon = a\delta^b$. But this does not effect the conclusion we have in (12).

Following consider this limit,

$$\begin{aligned}
& \lim_{\varepsilon,\delta\to 0}(1-\frac{1}{d/\varepsilon})^{d/\delta} \\
= & \lim_{\varepsilon,\delta\to 0} e^{d/\delta\ln(1-\frac{1}{d/\varepsilon})} \\
= & \lim_{\varepsilon,\delta\to 0} e^{\frac{\ln(\frac{d-\varepsilon}{d})}{\delta/d}} \\
= & \lim_{\varepsilon,\delta\to 0} e^{\frac{\frac{-1}{d-\varepsilon}}{1/d}} \\
= & e^{-1}
\end{aligned} \tag{12}$$

which means

$$P(x_\tau = x_n|x_r, x_g) = \lim_{\varepsilon,\delta\to 0} P(\check{x}_\tau \stackrel{t}{=} \check{x}_n|\check{x}_r, \check{x}_g)$$

$$= \begin{cases} 1-e^{-1} & x_r < x_n < x_g, x_g < x_n < x_r \\ 0 & \text{else} \end{cases} \tag{13}$$

Now, we propose our update rules for the *Discriminator* D with parameter θ to be optimized,

$$\theta \longrightarrow \theta + \nabla_\theta\{-|\nabla_{x_\tau} D^\theta(x_\tau) - \frac{x_r - x_g}{|x_r - x_g|}|^2\} \tag{14}$$

Lets take a look at it at a specific point, i.e., x_n,

$$\begin{aligned}
& \nabla_{x_\tau = x_n} D^\theta(x_\tau = x_n) \\
= & P(x_\tau = x_n|x_g < x_n < x_r)P(x_g < x_n < x_r) \\
& -P(x_\tau = x_n|x_r < x_n < x_g)P(x_r < x_n < x_g)
\end{aligned} \tag{15}$$

Since (13), we know that

$$P(x_\tau = x_n|x_g < x_n < x_r) = 1 - e^{-1} \tag{16}$$

$$P(x_\tau = x_n|x_r < x_n < x_g) = 1 - e^{-1} \tag{17}$$

Finally, we have,

$$\begin{aligned}
& \nabla_{x_\tau = x_n} D^\theta(x_\tau = x_n) \\
= & [P(x_g < x_n < x_r) - P(x_r < x_n < x_g)](1-e^{-1}) \\
= & [\int_0^{x_n} \mathbb{P}_g(x)dx \int_{x_n}^1 \mathbb{P}_r(x)dx) \\
& - \int_0^{x_n} \mathbb{P}_r(x)dx \int_{x_n}^1 \mathbb{P}_g(x)dx)](1-e^{-1}) \\
= & [\int_{x_n}^1 \mathbb{P}_r(x)dx - \int_{x_n}^1 \mathbb{P}_g(x)dx](1-e^{-1})
\end{aligned} \tag{18}$$

Now, we can give the update rule of *Generator* G with parameter β to be learnt,

$$\begin{aligned}
& \beta \\
\longrightarrow & \beta + \nabla_\beta\{-D^\theta(G^\beta(x_g))\} \\
\longrightarrow & \beta + \{-[\int_{x_g}^1 \mathbb{P}_r(x)dx - \int_{x_g}^1 \mathbb{P}_g(x)dx](1-e^{-1})(\nabla_\beta G^\beta(x_g))\}
\end{aligned} \tag{19}$$

which means where ever x_g is, it is updating itself to make $\int_{x_g}^1 \mathbb{P}_g(x)dx$ approaching $\int_{x_g}^1 \mathbb{P}_r(x)dx$. The absolute error when updating G, is actually modelling the proposed S distance.