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**Faculty of Mining, Ecology, Process Control
and Geotechnologies**

Institute of Control and Informatization of Production
Processes

**Mathematical methods and tools for
the management and computerization
of processes**

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Chapter 1

Introduction

Predictive modeling is essential across various disciplines, aiming to forecast future outcomes based on historical data and underlying patterns. Linear models, like linear regression, assume a straightforward relationship between input and output variables, making them interpretable and computationally efficient. Nonlinear models, such as neural networks and decision trees, capture more complex relationships but may require more computational resources.

In addition to linear and nonlinear models, behavioral prediction models are gaining prominence. These models integrate psychological, sociological, and behavioral factors to predict human behavior. They aim to understand and anticipate human decision-making processes, providing valuable insights in fields like marketing, public health, and economics.

In this material, we'll look on prediction models from mathematical point of view. We'll show basic usage and computations of that models and describe the mechanism of controlling of them.

Chapter 2

Prediction models

2.1 Linear Regression Models

Linear prediction models are a class of statistical models that assume a linear relationship between the input variables and the target variable. These models are widely used for prediction and inference in various fields such as statistics, machine learning, economics, and social sciences.

The general form of a linear prediction model can be represented as:

$$Y = \beta_0 + \beta_1 X_1 + \beta_2 X_2 + \dots + \beta_p X_p + \epsilon, \quad (2.1)$$

where

Y is the target variable,

X_1, X_2, \dots, X_p are the input variables (also known as predictors or features),

$\beta_0, \beta_1, \dots, \beta_p$ are the coefficients (parameters) representing the strength and direction of the linear relationship between each predictor and the target variable,

ϵ is the error term representing the difference between the observed and predicted values, assumed to follow a normal distribution with mean zero and constant variance.

Linear prediction models can be categorized into different types based on their specific characteristics and applications. Some common types of linear prediction models [12, 7].

Simple Linear Regression

A basic linear model with a single predictor variable.

Multiple Linear Regression

Extends simple linear regression to include multiple predictor variables.

Generalized Linear Models (GLMs)

A broad class of linear models that allow for non-normal error distributions and non-linear relationships between predictors and the response variable.

Ridge Regression and Lasso Regression

Regularized linear regression techniques used for dealing with multicollinearity and feature selection.

Linear prediction models offer several advantages, including interpretability, ease of implementation, and computational efficiency. However, they also have limitations, such as the assumption of linearity and the inability to capture complex non-linear relationships between variables [11].

Despite these limitations, linear prediction models remain a powerful and versatile tool for predictive modeling and inference in various domains.

Linear prediction models, such as linear regression, assume a linear relationship between the input variables \mathbf{x} and the target variable y . Mathematically, the linear regression model can be expressed as:

$$y = \beta_0 + \beta_1 x_1 + \beta_2 x_2 + \dots + \beta_p x_p + \epsilon, \quad (2.2)$$

where

y is the target variable,

x_1, x_2, \dots, x_p are the input variables (or predictors),

$\beta_0, \beta_1, \dots, \beta_p$ are the coefficients (parameters) representing the slope of the linear relationship between each predictor and the target variable,

ϵ is the error term representing the difference between the actual and predicted values, assumed to be normally distributed with mean zero and constant variance.

The goal of linear regression is to estimate the coefficients $\beta_0, \beta_1, \dots, \beta_p$ that

minimize the sum of squared errors (SSE), given a dataset $\{(x_i, y_i)\}_{i=1}^n$. This is typically done using the method of least squares, where the coefficients are chosen to minimize the sum of the squared differences between the observed and predicted values:

$$\hat{\beta} = \arg \min_{\beta} \sum_{i=1}^n (y_i - (\beta_0 + \beta_1 x_{i1} + \beta_2 x_{i2} + \dots + \beta_p x_{ip}))^2 \quad (2.3)$$

Once the coefficients are estimated, the model can be used to predict the target variable for new observations.

Simple Linear Regression

Simple Linear Regression is a basic linear prediction model that involves predicting a target variable y based on a single predictor variable x . The relationship between x and y is assumed to be linear, and it can be represented by the equation of a straight line:

$$y = \beta_0 + \beta_1 x + \epsilon, \quad (2.4)$$

where

y is the target variable,

x is the predictor variable,

β_0 is the intercept term, representing the value of y when x is zero,

β_1 is the slope coefficient, representing the change in y for a one-unit change in x ,

ϵ is the error term, representing the difference between the observed and predicted values, assumed to be normally distributed with mean zero and constant variance.

The goal of Simple Linear Regression is to estimate the parameters β_0 and β_1 that minimize the sum of squared errors (SSE) between the observed and predicted values of y . This is typically done using the method of least squares, where the coefficients are chosen to minimize the sum of the squared differences between the observed and predicted values:

$$\hat{\beta}_0, \hat{\beta}_1 = \arg \min_{\beta_0, \beta_1} \sum_{i=1}^n (y_i - (\beta_0 + \beta_1 x_i))^2 \quad (2.5)$$

Once the coefficients $\hat{\beta}_0$ and $\hat{\beta}_1$ are estimated, the model can be used to predict the target variable y for new observations based on their predictor variable x .

Multiple Linear Regression

Multiple Linear Regression is an extension of Simple Linear Regression that involves predicting a target variable y based on multiple predictor variables x_1, x_2, \dots, x_p . The relationship between the predictor variables and the target variable is assumed to be linear, and it can be represented by the equation:

$$y = \beta_0 + \beta_1 x_1 + \beta_2 x_2 + \dots + \beta_p x_p + \epsilon, \quad (2.6)$$

where

y is the target variable,

x_1, x_2, \dots, x_p are the predictor variables,

β_0 is the intercept term,

$\beta_1, \beta_2, \dots, \beta_p$ are the coefficients (parameters) representing the slopes of the linear relationships between each predictor variable and the target variable,

ϵ is the error term, representing the difference between the observed and predicted values, assumed to be normally distributed with mean zero and constant variance.

The goal of Multiple Linear Regression is to estimate the parameters $\beta_0, \beta_1, \dots, \beta_p$ that minimize the sum of squared errors (SSE) between the observed and predicted values of y . This is typically done using the method of least squares, where the coefficients are chosen to minimize the sum of the squared differences between the observed and predicted Value [witte2017statistics]:

$$\hat{\beta}_0, \hat{\beta}_1, \dots, \hat{\beta}_p = \arg \min_{\beta_0, \beta_1, \dots, \beta_p} \sum_{i=1}^n (y_i - (\beta_0 + \beta_1 x_{i1} + \beta_2 x_{i2} + \dots + \beta_p x_{ip}))^2 \quad (2.7)$$

Once the coefficients $\hat{\beta}_0, \hat{\beta}_1, \dots, \hat{\beta}_p$ are estimated, the model can be used to predict the target variable y for new observations based on their predictor variables x_1, x_2, \dots, x_p .

Generalized Linear Models (GLMs)

Generalized Linear Models (GLMs) are a broad class of linear models that extend the linear regression framework to handle a wider range of response

distributions and link functions. GLMs are particularly useful when the assumptions of normality and constant variance in linear regression are not met, or when the response variable is not continuous.

The general form of a GLM can be expressed as:

$$g(\mu) = \beta_0 + \beta_1 x_1 + \beta_2 x_2 + \dots + \beta_p x_p, \quad (2.8)$$

where

$g(\cdot)$ is the link function,

μ is the mean of the response variable,

x_1, x_2, \dots, x_p are the predictor variables,

$\beta_0, \beta_1, \dots, \beta_p$ are the coefficients (parameters) representing the slopes of the linear relationships between the predictors and the transformed mean.

GLMs consist of three components:

1. **Random Component:** Specifies the probability distribution of the response variable, which can be any member of the exponential family of distributions, such as normal, binomial, Poisson, gamma, etc.
2. **Systematic Component:** Represents the linear combination of predictor variables through the link function.
3. **Link Function:** Connects the mean of the response variable to the linear combination of predictors. It allows for modeling non-linear relationships between predictors and the response.

The parameters of a GLM are estimated using maximum likelihood estimation or iterative weighted least squares.

Once the model is fitted, predictions can be made for new observations using the same link function and parameter estimates.

Ridge Regression and Lasso Regression

Ridge Regression and Lasso Regression are regularization techniques used in linear regression to address multicollinearity and perform feature selection. They add a penalty term to the ordinary least squares (OLS) cost function to shrink the coefficients towards zero.

Ridge Regression

Ridge Regression adds a penalty term proportional to the square of the magnitude of the coefficients (β) to the OLS cost function. The objective function for Ridge Regression can be expressed as:

$$\text{minimize } J(\beta) = \sum_{i=1}^n (y_i - \beta_0 - \sum_{j=1}^p \beta_j x_{ij})^2 + \lambda \sum_{j=1}^p \beta_j^2, \quad (2.9)$$

where

y_i is the target variable for the i th observation,

x_{ij} is the value of the j th predictor for the i th observation,

$\beta_0, \beta_1, \dots, \beta_p$ are the coefficients to be estimated,

λ is the regularization parameter that controls the amount of shrinkage.

Lasso Regression

Lasso Regression adds a penalty term proportional to the absolute value of the magnitude of the coefficients (β) to the OLS cost function. The objective function for Lasso Regression can be expressed as:

$$\text{minimize } J(\beta) = \sum_{i=1}^n (y_i - \beta_0 - \sum_{j=1}^p \beta_j x_{ij})^2 + \lambda \sum_{j=1}^p |\beta_j|, \quad (2.10)$$

where

y_i is the target variable for the i th observation,

x_{ij} is the value of the j th predictor for the i th observation,

$\beta_0, \beta_1, \dots, \beta_p$ are the coefficients to be estimated,

λ is the regularization parameter that controls the amount of shrinkage.

Ridge Regression tends to shrink the coefficients towards zero but rarely sets them exactly to zero, while Lasso Regression can produce sparse models by setting some coefficients to exactly zero, effectively performing feature selection.

The choice between Ridge and Lasso regression depends on the specific characteristics of the dataset and the desired properties of the resulting model.

2.2 Linear prediction

Linear prediction is a method, that is extensively employed in signal processing to forecast future values of a time series by analyzing past observations. This technique is based on the premise that the current sample of a signal can be described by a linear combination of previous values complemented by a noise term [13, 5]. Long-term linear prediction extends this methodology using not only samples from the current past but also long-term instances, a longer period away, such as months or years. Although requiring a greater volume of data and increasing the complexity in comparison to short-term prediction, its applicability finds use in diverse fields such as weather forecasting, finance, economics and marketing to make long-term projections about variables such as sales, demand, or stock prices, with the goal to provide a comprehensive and accurate forecast that can be used to make strategic decisions in the long term [10].

2.2.1 Short-term linear prediction

Short-term linear prediction focuses on forecasting the immediate future values in a sequence. The model representation involves approximating a time series as a linear combination of its past values, providing a foundation for estimating the next value [11]. Is a technique commonly used in signal processing and time-series analysis to predict future values in a sequence based on a linear model. The basic idea is to use past observations in a sequence to estimate the next value. Linear prediction is a statistical technique used to forecast future values based on past observations. It is a method for modeling the relationship between a dependent variable and one or more independent variables in a linear form. The goal of linear prediction is to find the best linear approximation of the relationship between the variables, which can then be used to make predictions about future values of the dependent variable.

2.2.2 Parameters estimation

Parameter estimation in linear prediction involves determining the coefficients of a linear model that best represents a given dataset. In the context of linear prediction, this typically refers to estimating the coefficients of a linear filter that minimizes prediction error.

Least Squares Estimation

Minimize the sum of squared prediction errors between the model predictions and the actual observations.

Maximum Likelihood Estimation

Find the parameters that maximize the likelihood of observing the given data under the assumed model distribution.

Yule-Walker Equations

For AR models, the Yule-Walker equations provide a set of linear equations that can be solved to directly estimate the AR coefficients.

Burg Algorithm

An iterative algorithm that estimates AR coefficients by minimizing a reflection coefficient criterion.

Levinson-Durbin recursion

specific algorithm used for parameter estimation in linear prediction, particularly for autoregressive (AR) models

Assume we have a time series $x[n]$ that we want to model using an autoregressive model of order p , which can be represented as:

$$x[n] = \sum_{i=1}^p a_i x[n-i] + w[n], \quad (2.11)$$

where

a_i are the coefficients of the AR model,
 $w[n]$ is white noise, and p is the order of the model.

Toeplitz Matrix Formation arrange the autocorrelation values of the time series into a Toeplitz matrix R of size $(p+1) \times (p+1)$. The i -th row and

j -th column of this matrix represent the autocorrelation value at lag $|i - j|$.

The Levinson-Durbin algorithm is a recursive method that efficiently computes the AR coefficients a_i using the autocorrelation values stored in the Toeplitz matrix R . The recursion starts with an initial guess for the first coefficient a_1 and iteratively computes the subsequent coefficients using the following steps:

- set $k = 1$ and $E_0 = R[0, 0]$.
- compute the forward prediction error ϵ_k and reflection coefficient k_k using the formula:

$$\epsilon_k = R[k, k] - \sum_{j=1}^{k-1} a_j R[k - j, k] \quad (2.12)$$

$$k_k = \frac{\epsilon_k}{E_{k-1}} \quad (2.13)$$

- update the AR coefficients a_k using the reflection coefficient k_k :

$$a_k = k_k \quad (2.14)$$

- update the prediction error E_k :

$$E_k = (1 - k_k^2) E_{k-1} \quad (2.15)$$

- increment k and repeat the process until all coefficients are computed.

Once all p coefficients are computed, you obtain the AR model parameters a_1, a_2, \dots, a_p . The Levinson-Durbin recursion provides an efficient way to estimate the parameters of an autoregressive model by recursively solving linear equations, making it widely used in signal processing, time series analysis, and speech processing applications.

Overall, parameter estimation in linear prediction involves a systematic approach to finding the coefficients of a linear model that best fits the data and minimizes prediction error. It requires careful consideration of the model assumptions, choice of estimation method, and evaluation of model performance.

2.3 Non-linear Prediction models

Nonlinear prediction models are mathematical frameworks used to capture complex relationships between input variables and the target variable in prediction tasks. Unlike linear models, which assume a linear relationship between predictors and the target, nonlinear models can capture more intricate patterns in the data. Here's an overview of some common nonlinear prediction models [4].

Polynomial Regression

Polynomial regression fits a polynomial function to the data, allowing for curved relationships between predictors and the target variable.

$$y = \beta_0 + \beta_1x + \beta_2x^2 + \dots + \beta_nx^n + \epsilon \quad (2.16)$$

Generalized Additive Models (GAMs)

GAMs extend linear models by allowing for the inclusion of nonlinear functions of predictors, such as splines or smoothing functions.

$$y = f_1(x_1) + f_2(x_2) + \dots + f_p(x_p) + \epsilon \quad (2.17)$$

Decision Trees

Decision trees recursively partition the feature space into regions, making predictions based on the majority class or average target value of the instances within each region.

Random Forests

Random forests are ensemble learning methods that combine multiple decision trees to improve predictive performance. Each tree is trained on a random subset of the data and features.

Support Vector Machines (SVM)

SVMs find the hyperplane that best separates the classes or approximates the decision boundary in regression tasks. They can use kernel functions to handle nonlinear relationships.

Neural Networks

Neural networks are inspired by the neural architecture of the human brain, consisting of interconnected neurons organized into layers. These networks process raw data from the input layer through hidden layers, which perform computations and adjust weights to yield predictions. Ultimately, the output layer provides the final result in the form of parameter prediction or classification [14]. Neural networks are trained on large datasets using a process called backpropagation, which adjusts the weights and biases of the neurons to minimise the error between the predicted output and the actual output. Once a neural network has been trained, it can be used to make predictions on new data [9].

An artificial neuron or a perceptron (Fig. 2.1) is a basic building block of a neural network, that is modelled based on the biological neurons in the human brain, that receive input signals from other neurons, process them, and send the output signals to other neurons.

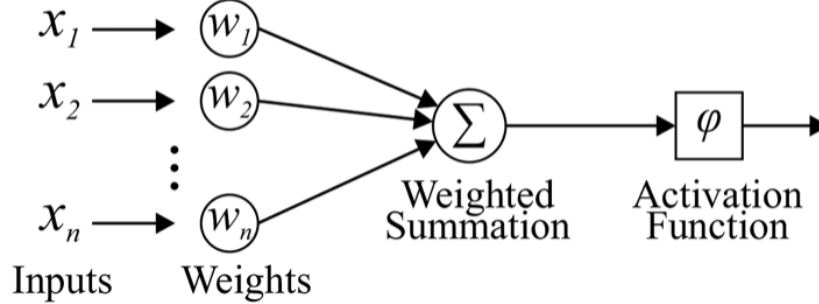


Figure 2.1: Perceptron preview [8].

Each input x_n undergoes weighting by the corresponding weight w_n before entering the summation stage. Subsequently, the weighted summation is transmitted to the activation unit, which generates the neuron's output signal.

Gaussian Processes

Gaussian processes are probabilistic models that represent distributions over

functions. They are particularly useful for modeling uncertainty and can capture complex nonlinear patterns in the data.

These nonlinear prediction models offer flexibility in capturing intricate relationships in the data and are widely used in various fields such as finance, healthcare, engineering, and more. Choosing the appropriate model depends on the specific characteristics of the data and the task at hand.

2.3.1 Long-term linear prediction

Long-term linear prediction (LTLP) refers to the use of linear prediction techniques to make predictions about the future values of a time series over an extended period of time [3], typically several months to several years. Unlike short-term linear prediction, which focuses on forecasting the near-term future, long-term linear prediction aims to provide a more comprehensive and accurate forecast of future values. Combining these two components, short-term and long-term, one obtains the relation [13, 1]:

$$\hat{x}(n) = \sum_{i=1}^p a_i x(n-i) + \sum_{i=-q}^q b_i x(n-i-Q), \quad (2.18)$$

where $\hat{x}(n)$ is the predicted value of the signal at instance n , p is the order of the short-term predictor, that uses p past samples, q is the order of the long-term predictor, that uses $2q+1$ samples a pitch period (Q) away, and a_i , b_i , are the short-term predictor coefficients, the long-term predictor coefficients, respectively (see Fig. 2.2).

2.4 Linear Model with Transportation Delay

A linear model with transportation delay is used to model situations where there is a linear relationship between input variables and the output variable, but the output has a time delay caused by the transportation system or process. This model can be expressed as:

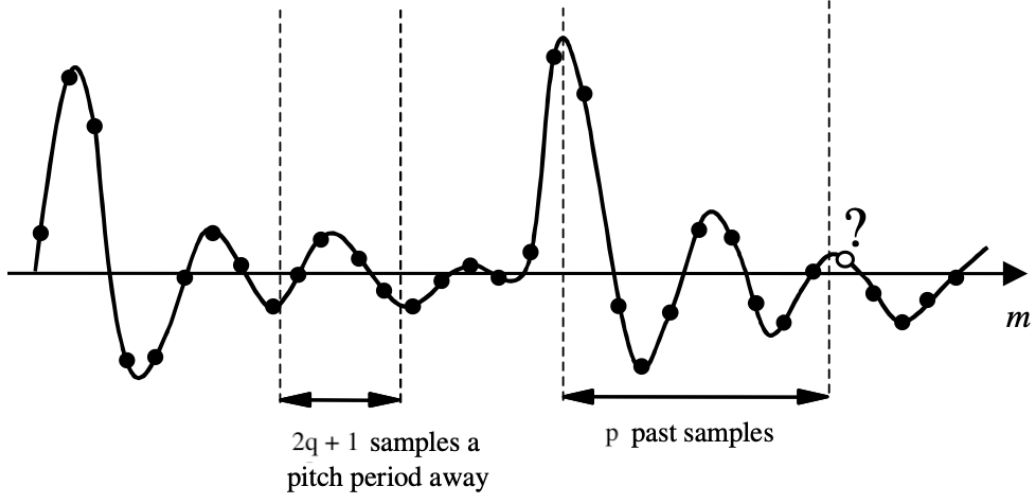


Figure 2.2: Pitch-lag in long-term prediction [3].

$$y(t) = \beta_0 + \beta_1 x(t - \tau) + \epsilon, \quad (2.19)$$

where

$y(t)$ is the output variable at time t ,

$x(t - \tau)$ is the input variable at time $t - \tau$, where τ is the transportation delay,

β_0 and β_1 are the coefficients of the model,

ϵ is the model error.

This model is used, for example, in modeling signals in telecommunications or in modeling dynamic systems with time delays.

2.5 Non-linear Model with Transportation Delay

A nonlinear model with transportation delay extends the linear model by allowing nonlinear relationships between input and output variables and also includes time delay caused by the transportation system. This model can be generally expressed as:

$$y(t) = f(x(t - \tau), \theta) + \epsilon, \quad (2.20)$$

where

$y(t)$ is the output variable at time t ,

f is a nonlinear function,

τ is the transportation delay

θ are the parameters of the nonlinear model,

ϵ is the model error.

Non-linear models with transportation delay are used in various fields, including biology, economics, and engineering, where it is important to model complex dynamic systems with time delays and nonlinearities. These models can better capture reality and provide more accurate predictions than linear models.

2.6 Behavioral models

Behavioral model are based on several different theories which simulates the behavioral systems.

2.6.1 Game Theory

Game theory is a mathematical framework for analyzing strategic interactions between rational decision-makers. It models situations where the outcome of one agent's actions depends on the actions of others. Game theory is used to study various aspects of human behavior, including cooperation, competition, bargaining, and negotiation.

Mathematical overview of Game Theory:

Players

In a game, there are n players, denoted by $N = \{1, 2, \dots, n\}$.

Strategies

Each player i has a set of strategies S_i , representing all possible actions or choices available to that player. A strategy s_i for player i is an element of

S_i , and a strategy profile $s = (s_1, s_2, \dots, s_n)$ represents a complete set of strategies chosen by all players.

Payoffs

The payoff function $u_i : S_1 \times S_2 \times \dots \times S_n \rightarrow \mathbb{R}$ specifies the utility or payoff that player i receives for choosing strategy s_i given that the other players choose strategies $s_{-i} = (s_1, s_2, \dots, s_{i-1}, s_{i+1}, \dots, s_n)$. Mathematically, it can be written as:

$$u_i(s_1, s_2, \dots, s_n) \quad (2.21)$$

Equilibrium Concepts

1. Nash Equilibrium (NE) A strategy profile $s^* = (s_1^*, s_2^*, \dots, s_n^*)$ is a Nash equilibrium if, for each player i , their strategy s_i^* maximizes their payoff given the strategies chosen by the other players s_{-i}^* . Mathematically, for each player i , we have:

$$u_i(s_i^*, s_{-i}^*) \geq u_i(s_i, s_{-i}^*) \quad \forall s_i \in S_i \quad (2.22)$$

2. Subgame Perfect Equilibrium (SPE) In dynamic games, a strategy profile s^* is a subgame perfect equilibrium if it represents a Nash equilibrium in every subgame of the original game. This ensures that each player's strategy is optimal not only in the current stage but also in every possible future stage of the game.
3. Bayesian Nash Equilibrium (BNE) In games with incomplete information, where players have private information, a strategy profile s^* is a Bayesian Nash equilibrium if, for each player i , their strategy s_i^* maximizes their expected payoff given their beliefs about the other players' types or characteristics.

These equations provide the mathematical foundation for analyzing strategic interactions in Game Theory, enabling the identification of stable outcomes and predicting the behavior of rational decision-makers in various contexts.

2.6.2 Utility Theory

Utility theory is a mathematical framework for representing and analyzing individual preferences and decision-making under uncertainty. It assumes that individuals make decisions to maximize their utility, where utility represents the subjective value or satisfaction derived from different outcomes. Utility theory is often used in economics and decision theory to model and predict human behavior.

Utility theory is a branch of economics that deals with how individuals make choices based on their preferences and the trade-offs they face. The fundamental concept in utility theory is the notion of utility, which represents the satisfaction or happiness a person derives from consuming a good or experiencing an outcome.

Utility Function

A utility function, typically denoted by $U(x)$, maps consumption bundles (combinations of goods or outcomes) to a numerical representation of the utility or satisfaction derived from consuming that bundle. Mathematically, it can be represented as:

$$U(x_1, x_2, \dots, x_n), \quad (2.23)$$

where

x_1, x_2, \dots, x_n are the quantities of different goods or outcomes in the consumption bundle.

Total Utility

Total utility is the overall level of satisfaction or happiness obtained from consuming a particular set of goods or experiencing a particular outcome. It is the sum of the utilities derived from each individual good or outcome.

$$TU = U(x_1) + U(x_2) + \dots + U(x_n) \quad (2.24)$$

Marginal Utility

Marginal utility represents the additional utility obtained from consuming

one additional unit of a good or experiencing one additional unit of an outcome, while holding the consumption of other goods constant. Mathematically, it is the derivative of the utility function with respect to the quantity of the good:

$$MU = \frac{dU}{dx}, \quad (2.25)$$

where

MU is the marginal utility,

dx is a small change in the quantity of the good.

Diminishing Marginal Utility

This principle states that as a person consumes more of a good, the additional satisfaction (or marginal utility) derived from each additional unit of the good decreases. Mathematically, it implies that the marginal utility function is decreasing:

$$\frac{d^2U}{dx^2} < 0 \quad (2.26)$$

These are some of the fundamental equations and concepts in utility theory. They help economists and decision-makers understand how individuals make choices based on their preferences and constraints.

2.6.3 Bayesian Decision Theory

Bayesian decision theory is a mathematical framework for decision-making under uncertainty, based on the principles of Bayesian probability theory. It models decisions as choices among possible actions, where each action has associated uncertain outcomes and probabilities. Bayesian decision theory provides a formal method for incorporating prior beliefs and updating them based on new evidence to make optimal decisions.

Prior Probability

Before observing any data, we have beliefs about the likelihood of different events occurring. This is represented by the prior probability distribution $P(\theta)$, where θ is a parameter representing the uncertain quantity.

Likelihood Function

Given a particular value of the parameter θ , the likelihood function $L(\theta|x)$ describes the probability of observing the data x . It represents how well the data supports different values of the parameter.

Posterior Probability

After observing the data x , we update our beliefs about the parameter θ using Bayes' theorem:

$$P(\theta|x) = \frac{L(\theta|x) \cdot P(\theta)}{P(x)}, \quad (2.27)$$

where

$P(\theta|x)$ is the posterior probability distribution, representing our updated beliefs about θ after observing the data x ,

$P(x)$ is the marginal likelihood or evidence, which acts as a normalization constant and ensures that the posterior distribution integrates to 1.

Decision Rule

A decision rule specifies how to choose an action based on the observed data and the posterior distribution. The decision rule could be to choose the action that maximizes expected utility.

Expected Utility

The expected utility of taking action a given the observed data is calculated as the weighted average of the utility of each possible outcome, where the weights are the probabilities of those outcomes given the data:

$$EU(a|x) = \sum_{\theta} P(\theta|x) \cdot U(a, \theta), \quad (2.28)$$

where

$EU(a|x)$ is the expected utility of action a given the data x ,

$U(a, \theta)$ is the utility of taking action a under parameter θ .

Decision Theory Loss Function

Decision theory often involves defining a loss function $L(a, \theta)$ that quantifies

the cost or loss associated with taking action a when the true parameter is θ . The goal is to minimize the expected loss.

These equations and concepts provide a framework for making decisions under uncertainty in a principled and rational manner, incorporating both prior beliefs and observed data.

2.6.4 Stochastic Models

Stochastic models are mathematical models that incorporate randomness or uncertainty into the modeling of human behavior. These models often use probability distributions to describe random variables and stochastic processes to model the evolution of these variables over time. Stochastic models are used to study various phenomena in human behavior, including risk-taking, decision-making under uncertainty, and the dynamics of social systems.

Stochastic Process

A stochastic process is a collection of random variables indexed by time or some other parameter. Mathematically, it is represented as $X(t)$, where t is the time parameter.

Probability Distribution

Stochastic models often involve probability distributions to describe the uncertainty associated with random variables. Common probability distributions include:

- Normal (Gaussian) distribution
- Poisson distribution
- Exponential distribution
- Binomial distribution
- Multinomial distribution
- Geometric distribution

Markov Chains

Markov chains are stochastic processes with the Markov property, which states that the future behavior of the process depends only on its current state and not on its past history. Mathematically, for a discrete-time Markov chain with states S and transition probabilities P , the Markov property is represented as:

$$P(X_{n+1} = j | X_n = i, X_{n-1} = i_{n-1}, \dots, X_0 = i_0) = P(X_{n+1} = j | X_n = i) \quad (2.29)$$

Continuous-Time Markov Chains (CTMC)

CTMCs are Markov chains where time is continuous. The transition rates between states are constant and independent of time. The master equation governs the evolution of the probability distribution of states over time in a CTMC.

Stochastic Differential Equations (SDEs)

SDEs describe the evolution of a stochastic process over continuous time. They are differential equations that involve both deterministic and stochastic components. A simple form of SDE is given by:

$$dX(t) = \mu(X(t), t) dt + \sigma(X(t), t) dW(t), \quad (2.30)$$

where

$X(t)$ is the stochastic process,

$\mu(X(t), t)$ represents the deterministic drift term,

$\sigma(X(t), t)$ represents the stochastic diffusion term,

$dW(t)$ is a Wiener process (Brownian motion), representing random fluctuations.

Ito's Lemma

Ito's Lemma is a formula used to find the differential of a function of a stochastic process. It extends the chain rule to include stochastic terms. For a function $f(X(t), t)$ of a stochastic process $X(t)$, Ito's Lemma is given by:

$$df(X(t), t) = \frac{\partial f}{\partial t} dt + \frac{\partial f}{\partial x} dX(t) + \frac{1}{2} \frac{\partial^2 f}{\partial x^2} (\sigma(X(t), t))^2 dt \quad (2.31)$$

These equations and concepts form the foundation of stochastic modeling and are used to describe and analyze systems subject to randomness or uncertainty.

2.6.5 Network Models

Network models are mathematical representations of social or relational structures, where nodes represent individuals or entities, and edges represent relationships or interactions between them. These models are used to study various aspects of human behavior, including social influence, information diffusion, and the spread of behaviors or diseases through social networks. Network analysis techniques, such as centrality measures and community detection algorithms, are used to analyze and interpret network data.

Graph Theory

Network models are often described using graph theory, where a graph $G = (V, E)$ consists of a set of vertices (nodes) V and a set of edges E that connect pairs of vertices. Mathematically, a graph can be represented as an adjacency matrix, A , where $A_{ij} = 1$ if there is an edge between nodes i and j , and $A_{ij} = 0$ otherwise [2, 6].

Degree Distribution

The degree of a node in a network is the number of edges incident to it. The degree distribution $P(k)$ gives the probability that a randomly chosen node has degree k . It can be characterized using mathematical functions such as power-law distributions, exponential distributions, or Poisson distributions.

Centrality Measures

Centrality measures quantify the importance of nodes within a network. Some common centrality measures include **Degree centrality** as the number of edges incident to a node. **Betweenness centrality** as the fraction of shortest paths that pass through a node. **Eigenvector centrality** as the influence of a node in the network, taking into account the centrality of its neighbors.

Random Graph Models

Random graph models are used to generate synthetic networks with specific structural properties. Examples include:

- Erdős-Rényi model: A random graph where each edge is present with a fixed probability.
- Barabási-Albert model: A preferential attachment model where new nodes are connected to existing nodes with probability proportional to their degree.
- Watts-Strogatz model: A small-world model where most nodes are connected to their nearest neighbors, with a small probability of rewiring edges to create shortcuts.

Network Dynamics

Network models can capture the dynamics of processes that unfold on networks. For example **Epidemic models**, which describe the spread of diseases or information through a network. **Diffusion models** to study the adoption of innovations or behaviors among individuals in a social network. **Opinion dynamics** to explore how opinions or beliefs evolve within a population through interactions on a network.

Network Optimization

In various applications, network models are used to optimize certain objectives subject to constraints. Optimization problems on networks can be formulated using mathematical programming techniques, such as linear programming, integer programming, or network flow algorithms.

These mathematical equations and concepts provide a foundation for analyzing and understanding the structure, function, and dynamics of complex networks in diverse fields.

Chapter 3

Controlling

Controlling a system from a mathematical and cybernetics perspective involves using mathematical models and principles of cybernetics to understand, analyze, and influence the behavior of the system. The first step in controlling a system is to develop a mathematical model that describes its behavior. This model may be based on physical laws, empirical data, or a combination of both. Depending on the complexity of the system, the model may be represented using differential equations, difference equations, state-space equations, or other mathematical formalisms. In many cases, the exact mathematical model of a system may not be known or may be too complex to use directly. In such cases, system identification techniques are used to estimate the parameters of the model from experimental data or observations of the system's behavior.

Control theory provides the mathematical framework for designing control strategies that regulate the behavior of a system to achieve desired objectives. This involves analyzing the system's dynamics, designing controllers, and evaluating their performance. Common control techniques include PID control, state feedback control, optimal control, and robust control.

Feedback control is a fundamental concept in cybernetics and control theory. It involves continuously monitoring the system's output and comparing it to a reference or desired setpoint. The difference, known as the error signal, is used to adjust the system's inputs or parameters in real-time to minimize the error and maintain desired performance.

Cybernetics Principles is the study of systems and processes that regulate themselves through feedback loops. From a cybernetic perspective, controlling a system involves understanding the system's structure, dynamics, and feedback mechanisms. Cybernetic principles such as homeostasis, adaptation, self-organization, and emergence are often used to analyze and design control systems.

Adaptive and Learning Control in many real-world applications, the parameters or dynamics of a system may change over time or may not be precisely known. Adaptive and learning control techniques are used to adjust the control strategy in real-time based on feedback from the system. These techniques allow control systems to adapt to changing conditions and improve performance over time.

Hierarchical Control in complex systems, control may be organized hierarchically, with multiple levels of control operating at different time scales or spatial scales. Hierarchical control architectures coordinate the actions of different controllers to achieve overall system objectives while respecting constraints and optimizing performance.

Networked Control Systems with the proliferation of networked sensors, actuators, and communication technologies, many control systems are now distributed across multiple interconnected components. Networked control systems pose unique challenges related to communication delays, data fusion, and network security, which must be addressed in the design of control strategies.

3.1 Linear and non-linear models

Controlling linear and nonlinear models involves designing control laws or strategies to achieve desired system behavior or performance. The mathematical approaches used for controlling such models vary depending on the specific characteristics of the system and the control objectives. Here are some common mathematical approaches for controlling linear and nonlinear models.

Linear Control Systems

State-Space Representation linear time-invariant (LTI) systems can be represented in state-space form as:

$$\begin{aligned}\dot{x} &= Ax + Bu \\ y &= Cx + Du,\end{aligned}\tag{3.1}$$

where

x is the state vector.

u is the control input.

y is the output.

A , B , C , and D are system matrices.

Transfer Function Representation, linear systems can also be represented in transfer function form, which relates the Laplace transforms of the input and output signals:

$$Y(s) = G(s)U(s),\tag{3.2}$$

where

$Y(s)$ and $U(s)$ are the Laplace transforms of the output and input, respectively.

$G(s)$ is the transfer function of the system.

Classical Control Theory such as PID (Proportional-Integral-Derivative) control, root locus, and frequency response analysis (e.g., Bode plots), are commonly used for linear systems. These techniques rely on algebraic and calculus-based methods for designing controllers to achieve desired performance criteria like stability, transient response, and steady-state error.

State Feedback Control in state-space representation, state feedback control involves designing a state feedback gain matrix K to stabilize the system or achieve certain performance objectives. Linear quadratic regulator (LQR) and pole placement methods are examples of state feedback control techniques.

Nonlinear Control Systems

Lyapunov Stability Analysis is often used to analyze the stability of nonlinear systems. It involves finding a Lyapunov function $V(x)$ that satisfies certain conditions to prove stability or asymptotic stability of equilibrium points.

Feedback Linearization is a technique used to transform a nonlinear system into a linear one through state feedback and input/output transformations. This approach enables the application of linear control techniques to nonlinear systems.

Sliding Mode Control is a nonlinear control technique that aims to drive the system state onto a predefined sliding surface. It involves designing a discontinuous control law to ensure robustness to system uncertainties and disturbances.

Model Predictive Control (MPC) is a versatile control strategy used for both linear and nonlinear systems. It involves solving an optimization problem at each time step to determine the control action that minimizes a cost function while satisfying system dynamics and constraints.

Adaptive Control techniques adjust controller parameters online to adapt to changes in system dynamics or uncertainties. These methods often rely on parameter estimation algorithms and adaptive laws to update controller gains.

Non-linear Observers are used to estimate the unmeasured states of a nonlinear system based on available measurements. Extended Kalman filters (EKFs) and sliding mode observers are examples of nonlinear observer designs.

These are some of the mathematical approaches commonly used for controlling both linear and nonlinear systems. The choice of approach depends on the specific characteristics of the system, the control objectives, and the available information about the system dynamics.

3.2 Behavioral models

Outer control of behavioral models involves managing the behavior of a system or agent at a higher level, typically focusing on achieving specific goals or objectives rather than directly manipulating the system's dynamics. This can involve designing strategies, policies, or interventions to influence the behavior of individuals, groups, or organizations. While behavioral models can be quite diverse, ranging from simple decision-making models to complex agent-based simulations.

Controlling of behavioral models depends of the type of the model used. In the sections and subsections 2.6.1, 2.6.2, 2.6.3, 2.6.4, 2.6.5 is shown the models equations which are used to control the models bahavior.

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