

## Probability: Definitions

### Def: Measurable mapping

Let  $\mathcal{A}, \mathcal{B}$  be  $\sigma$ -algebras in  $\Lambda, \Omega$ . A mapping  $X : \Lambda \rightarrow \Omega$  is called *measurable* if  $X^{-1}(B) \in \mathcal{A}$  for all  $B \in \mathcal{B}$ .

Interpretation: “ $F$  measurable” means that expression “ $\mathbb{P}(X^{-1}(B))$ ” makes sense.

### Def: Random variables

A *random variable*  $X$  is a measurable mapping from an abstract probability space  $(\Lambda, \mathcal{A}, \mathbb{P})$  into an observation space  $(\Omega, \mathcal{B}(\Omega))$ .

### Image Measure

The measure  $\mathbb{P}$  is not known explicitly. We work with **the distribution  $\mu_X$  of random variable  $X$**  defined as the *image measure*:

$$\mu_X := X(\mathbb{P}) \quad \text{i.e.} \quad \mu_X(A) := \mathbb{P}(X^{-1}(A))$$

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## Parametric Model

### Parametric model

Let  $X : (\Lambda, \mathcal{A}) \rightarrow (\Omega_X, \mathcal{B}_X)$  and  $\Theta : (\Lambda, \mathcal{A}) \rightarrow (\Omega_\Theta, \mathcal{B}_\Theta)$  be two random variables, and  $\mu_X = X(\mathbb{P})$ . Then the conditional distribution  $\mu_X(X|\Theta)$  is called a *parametric family* of models (parameterized by  $\theta \in \Omega_\Theta$ ).

### Bayesian model

If  $X$  observed and  $\Theta$  unobserved, we call:

- ▶  $\mu_\Theta := \Theta(\mathbb{P})$  the *prior measure*
- ▶  $\mu_\Theta(\Theta|X)$  the *posterior measure*
- ▶ The overall model is called a Bayesian model.

*Note:* Not defined by a Bayes equation!

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## Conditioning

### Note

Defining conditional measures requires some effort.

### Direct approach

Conditional probability of  $X(\omega) \in A$  given that  $X(\omega) \in B$ :

$$\mu(A|B) := \frac{\mu(A \cap B)}{\mu(B)}$$

→ no use if  $\mu(B) = 0$  (think of Bayesian model on  $\mathbb{R}^d$ )

### For now:

- ▶ We will just write  $\mu(X|Y)$  for the conditional probability of  $X$  given  $Y$  and forget about details.
- ▶ If  $X, Y$  have a joint density,  $\mu(X|Y)$  has a conditional density  $p(x|y)$ .

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## Bayes' Theorem

### Problem:

Given the prior and the data, how can we determine the posterior? (Without exhaustive knowledge of  $\mathbb{P}, \mathcal{A}$  etc)

### Bayes Theorem

If the sampling model  $\mu_X(X|\Theta)$  has density  $p_{X|\theta}$ , then:

$$\frac{d\mu_{\Theta|X}}{d\mu_\Theta}(\theta|x) = \frac{p_{X|\theta}}{\int p_{X|\theta} d\mu_\Theta(\theta)}$$

for all  $x$  with  $\int p_{X|\theta} d\mu_\Theta(\theta) \notin \{0, \infty\}$ .

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