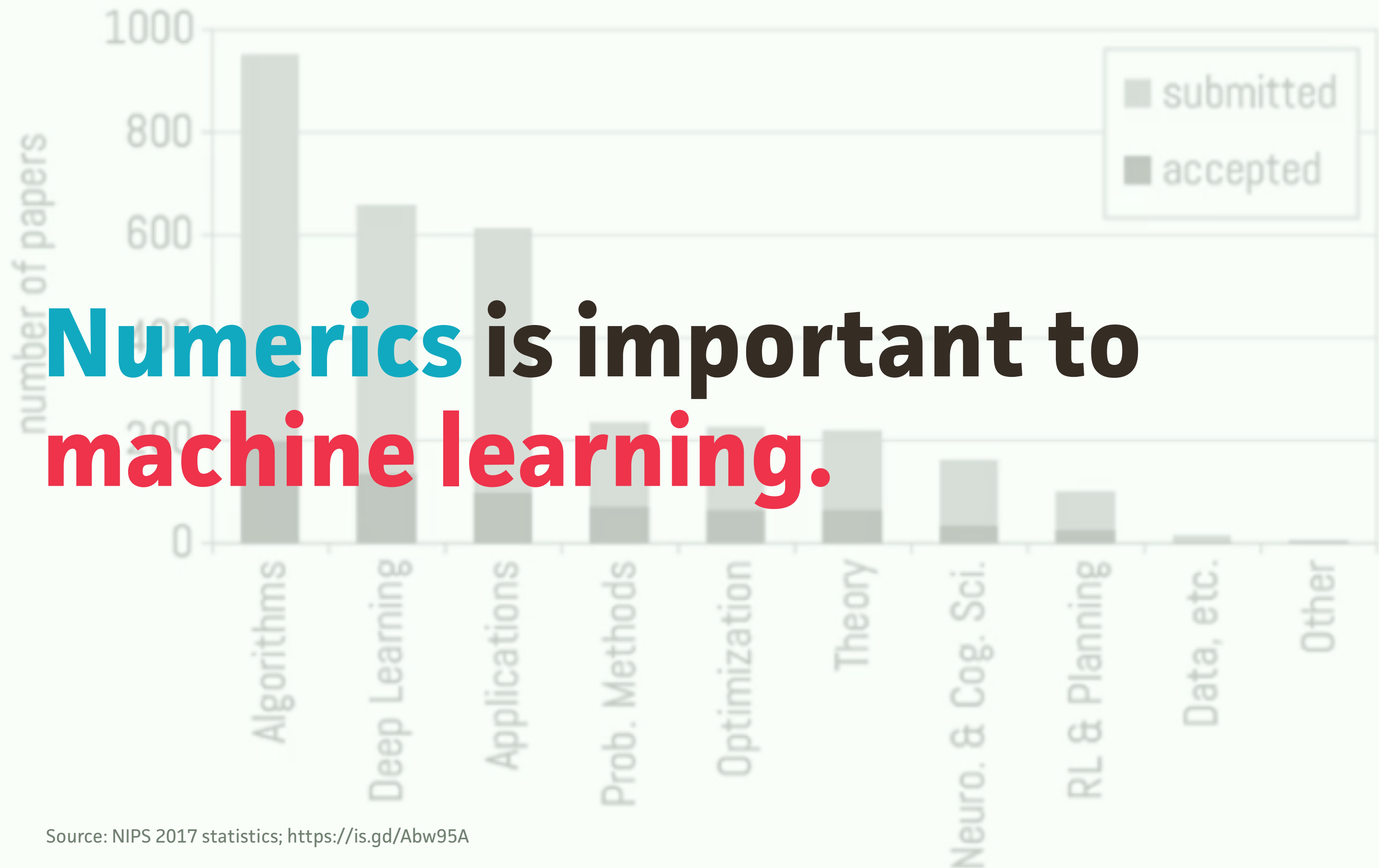


PROBABILISTIC NUMERICS: NANO-MACHINE-LEARNING

Michael A Osborne, @maosbot



Numerics is important to machine learning.

Which **numerics problems** have you needed solved in the **last month**?

1. Linear algebra.
2. Optimisation.
3. Global optimisation.
4. Integration.
5. Ordinary differential equations.

Tabula terræ Nouæ Zemblæ,
 in qua fretum sinusq; WAIGATS
 item ora littoralis TARTARIÆ atq;
 RUSSIÆ, ad urbem usq; KILDEINAM
 præscribitur adhuc CURSUS quem inde
 naues in reditu tenent secus septentrionale
 litus et TRAIECTUS
 prope fretum WAIGATS ad Rusiæ
 crain et ad promontorium CANDENOS
 atq; fauces usq; MARIS ALBI.
 AUTHORE GERHARDO DE VEER.



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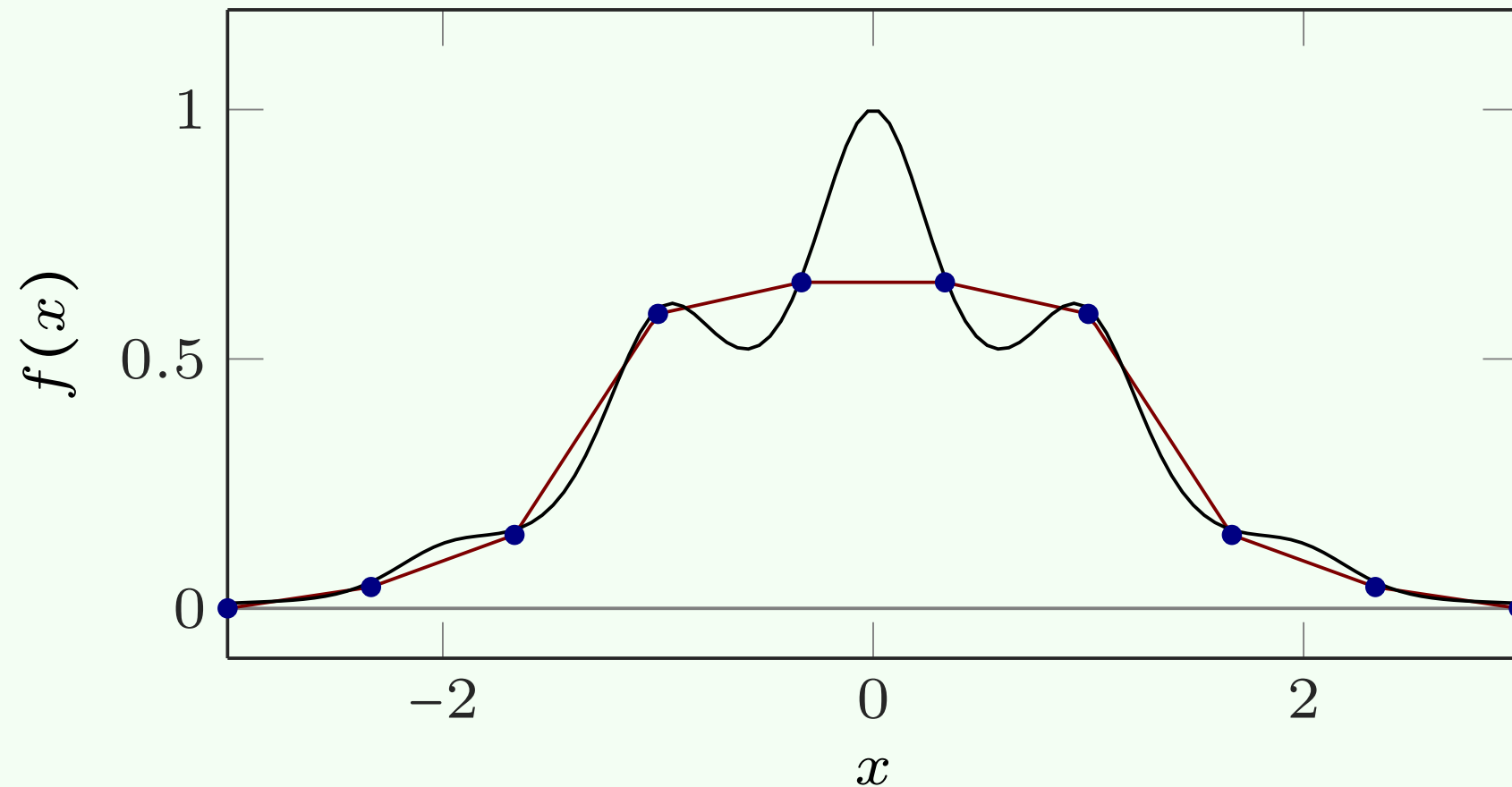
The answer to a
numeric problem can
only be **approximated**,

e.g.

$$F = \int_{-3}^3 f(x) dx$$

for

$$f(x) = \exp\left(-(\sin(3x))^2 - x^2\right).$$





**Machine learning treats
algorithms as agents.**

**Probabilistic numerics treats
numeric algorithms as agents.**

```
9 import numpy as np
10 import platform
11 import subprocess
12 import nlopt
13 from sklearn.utils import check_random_state
14 from scipy.stats import beta, norm
15
16
17 class RobotArm():
18     def __init__(self):
19         self.name = 'Robot Arm Simulator'
20         self.system = platform.system()
21
22     def abs_pos(self, jt_angle):
23         assert jt_angle.ndim == 1, 'jt_angle has to be one dimensional'
24         assert len(jt_angle) == 3, 'jt_angle has to have 3 inputs'
25
26         if self.system == 'windows':
27             args = str('./robot_arm ' + str(jt_angle[0]) + ' ' + str(jt_angle[1]) + ' ' + str(jt_angle[2]))
28             proc = subprocess.Popen(args, shell=True, stdout=subprocess.PIPE)
29         else:
30             args = str('robot_arm.exe ' + str(jt_angle[0]) + ' ' + str(jt_angle[1]) + ' ' + str(jt_angle[2]))
31             proc = subprocess.Popen(args, stdout=subprocess.PIPE)
32
33         output = proc.stdout
34         for line in output:
35             output = line
36         proc.kill()
37
38         return np.array([float(out) for out in output.split()])
```


As motivation:

- 1. numeric **error** is significant;**
- 2. numeric methods are **generic**;**
- 3. our numerics problems **tax**
our computation.**



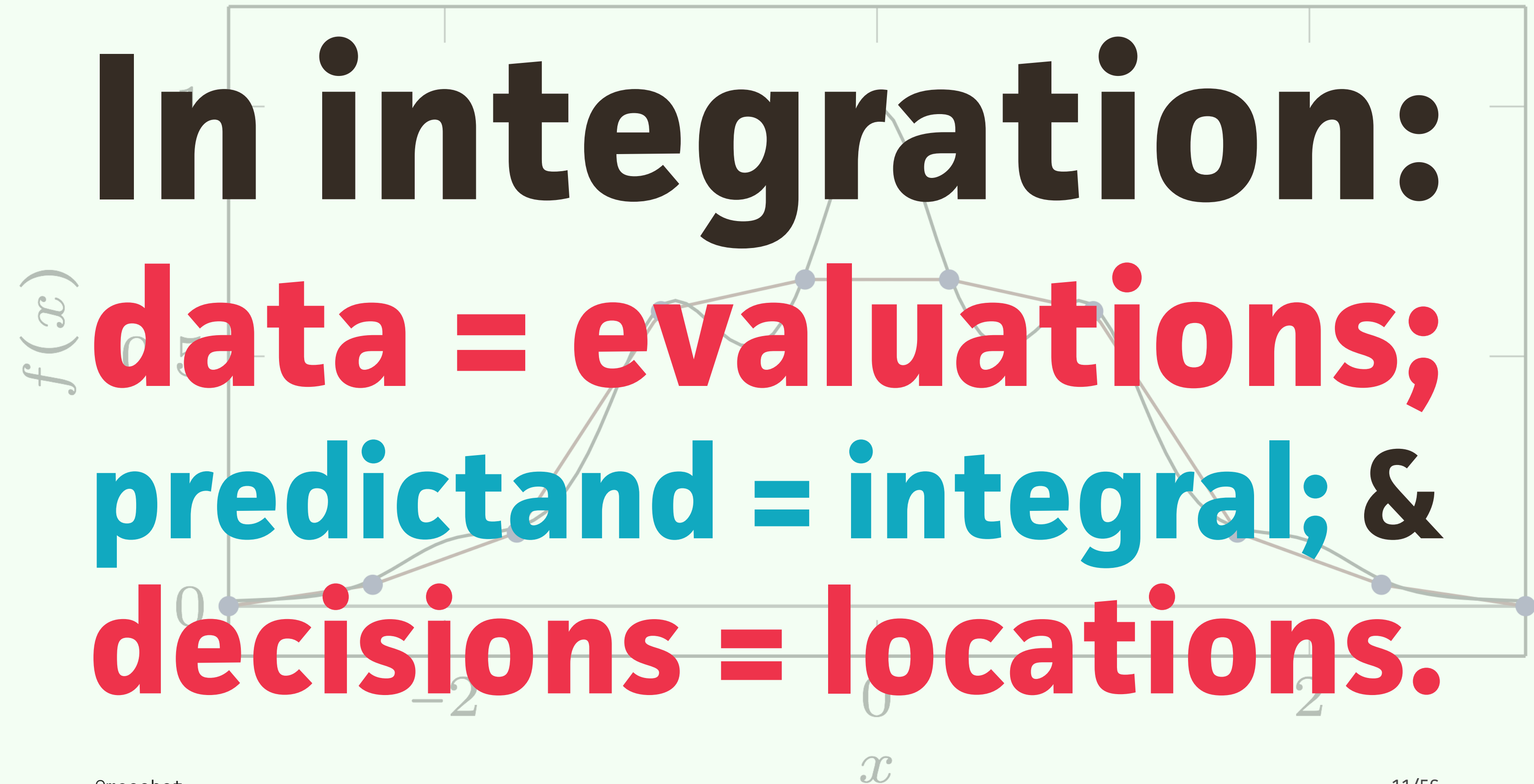
**An agent
receives data,
predicts, & then
makes decisions.**

In integration:

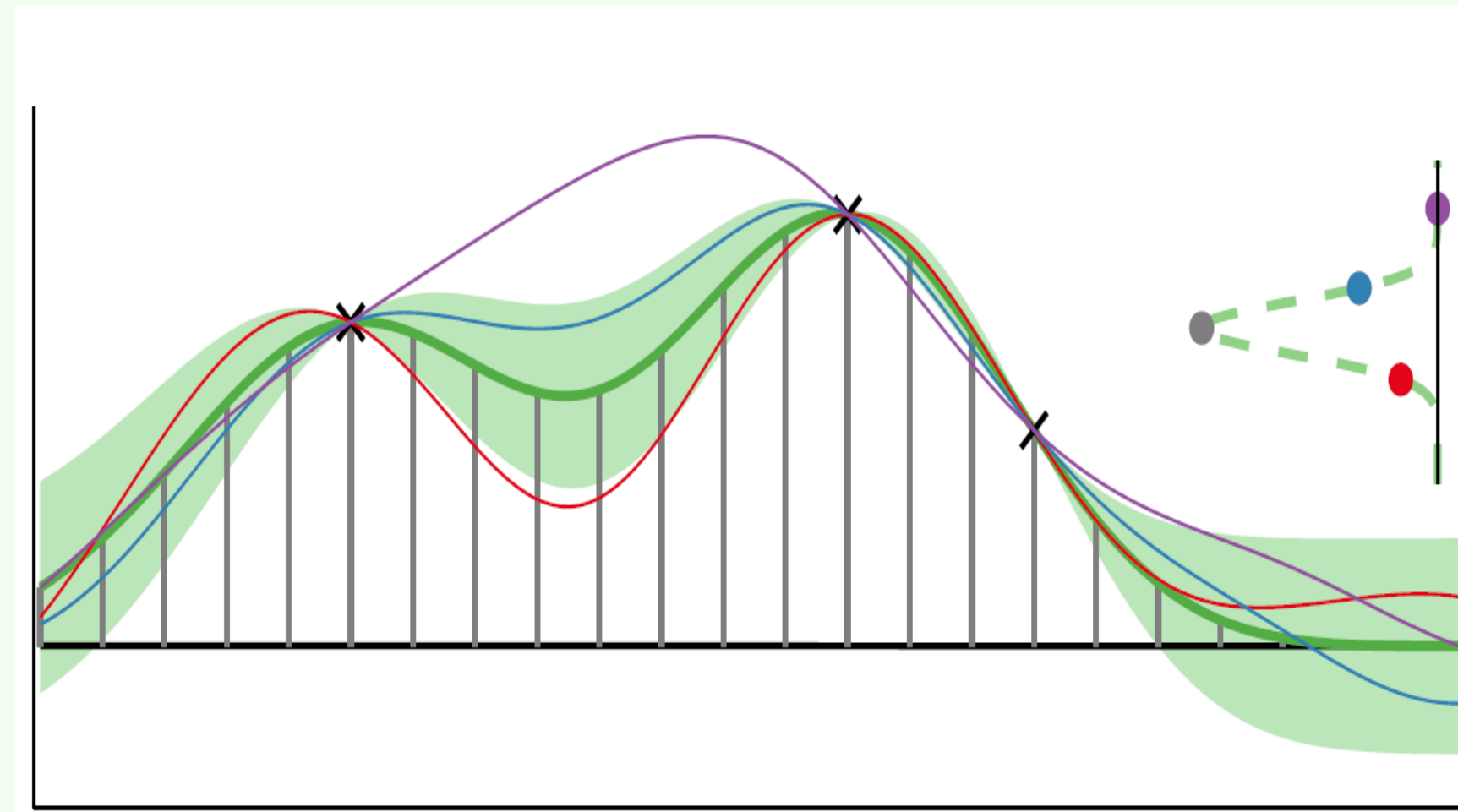
data = ?;


predictand = ?; &

decisions = ?.



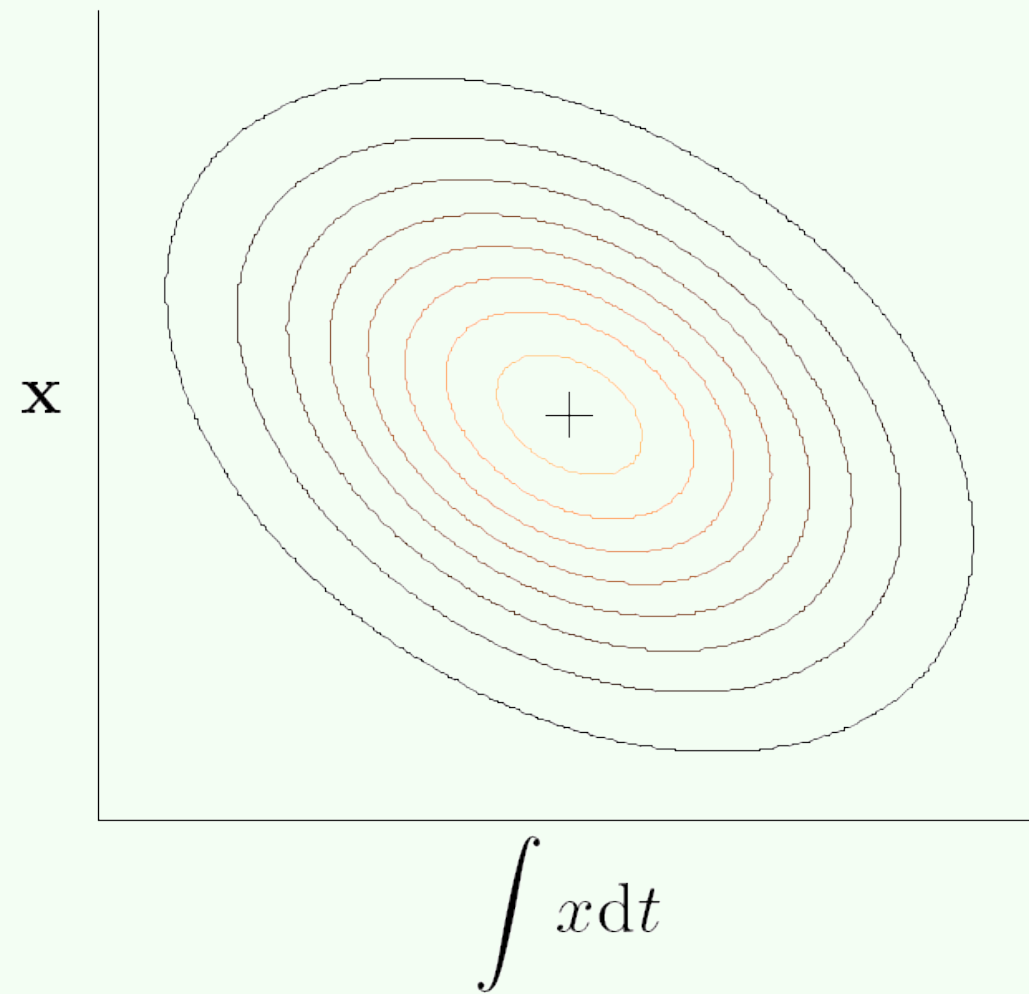
**Bayesian
quadrature is
probabilistic
numerics for
integration.**

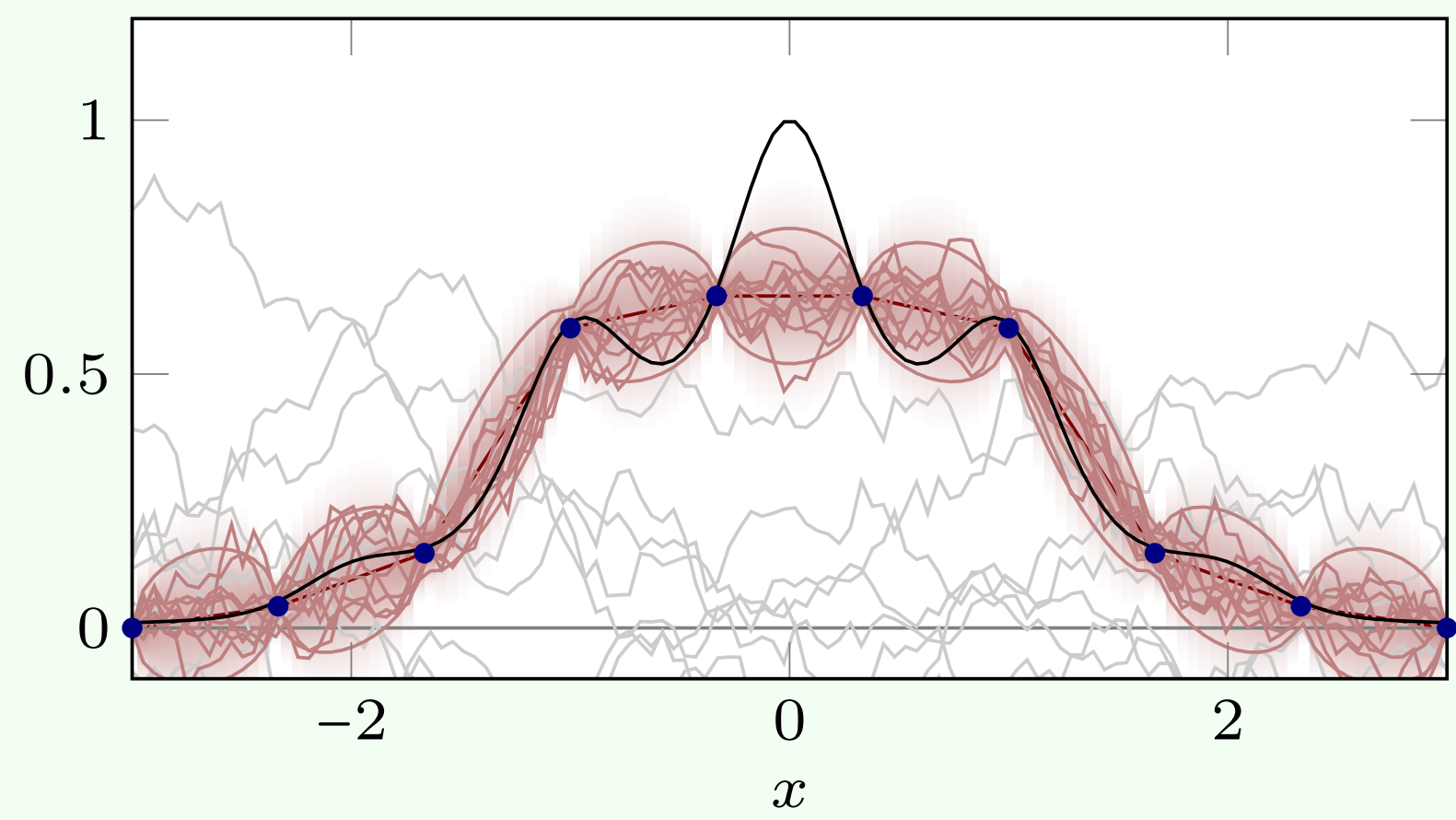
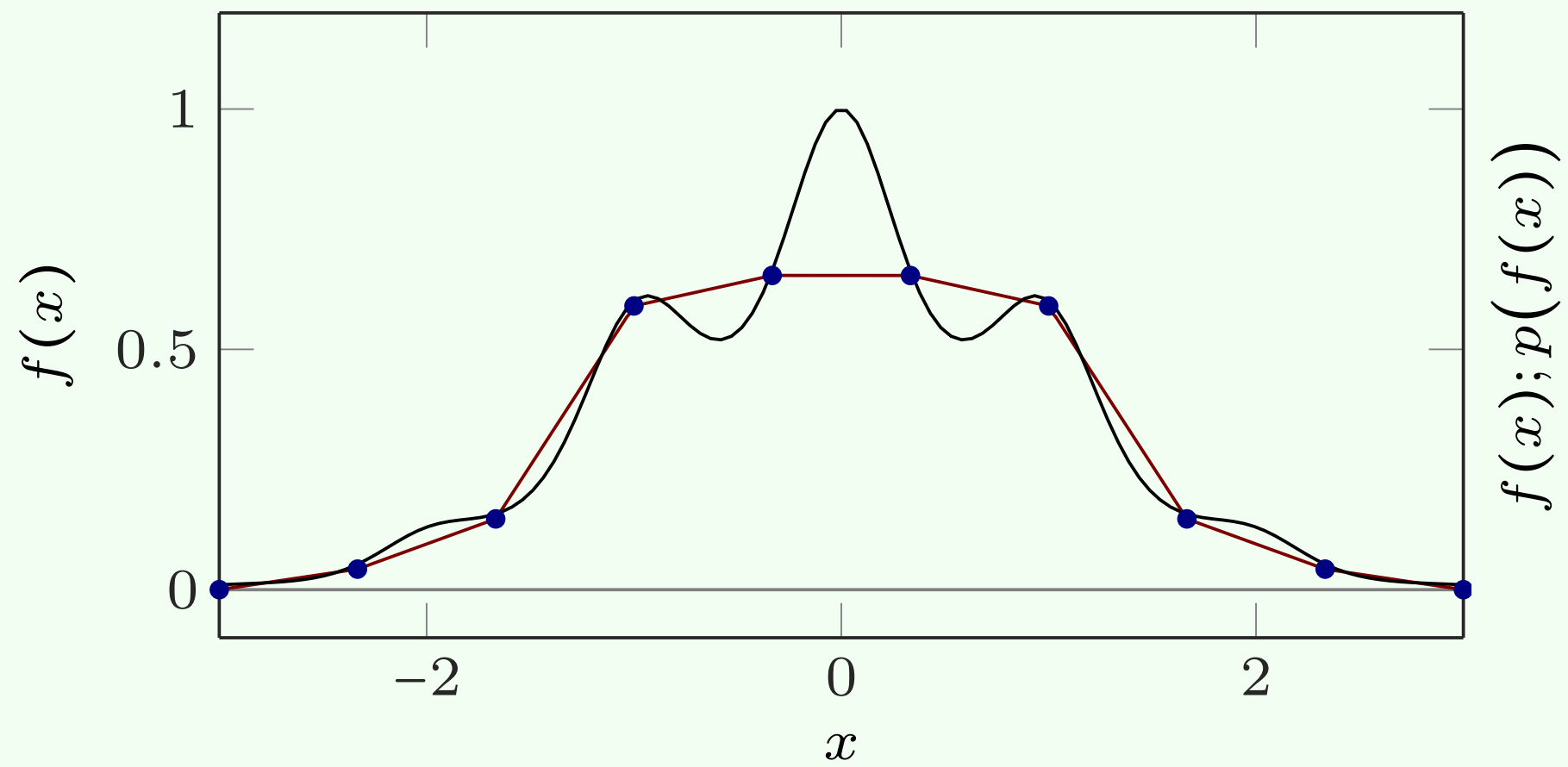




**An agent is defined by
its **prior** and
loss function.**

With a **Gaussian process** prior for the integrand, the **integral is joint Gaussian**.





The trapezoidal rule is the posterior mean estimate for the integral

$$F = \int_a^b f(x) \, dx$$

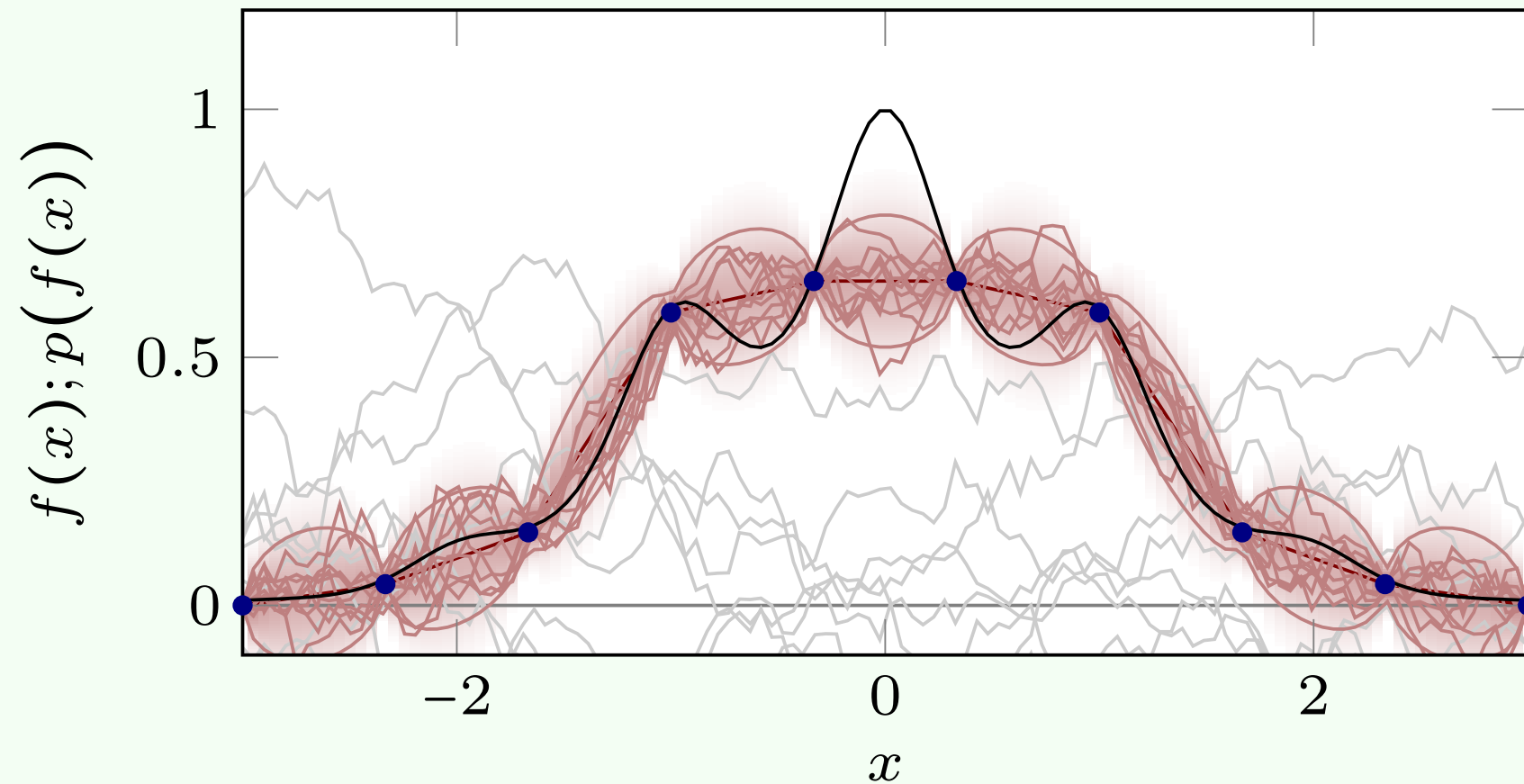
under any centered Wiener process prior

$$p(f) = \mathcal{GP}(f; 0, k)$$

with

$$k(x, x') = \theta^2 (\min(x, x') - \chi)$$

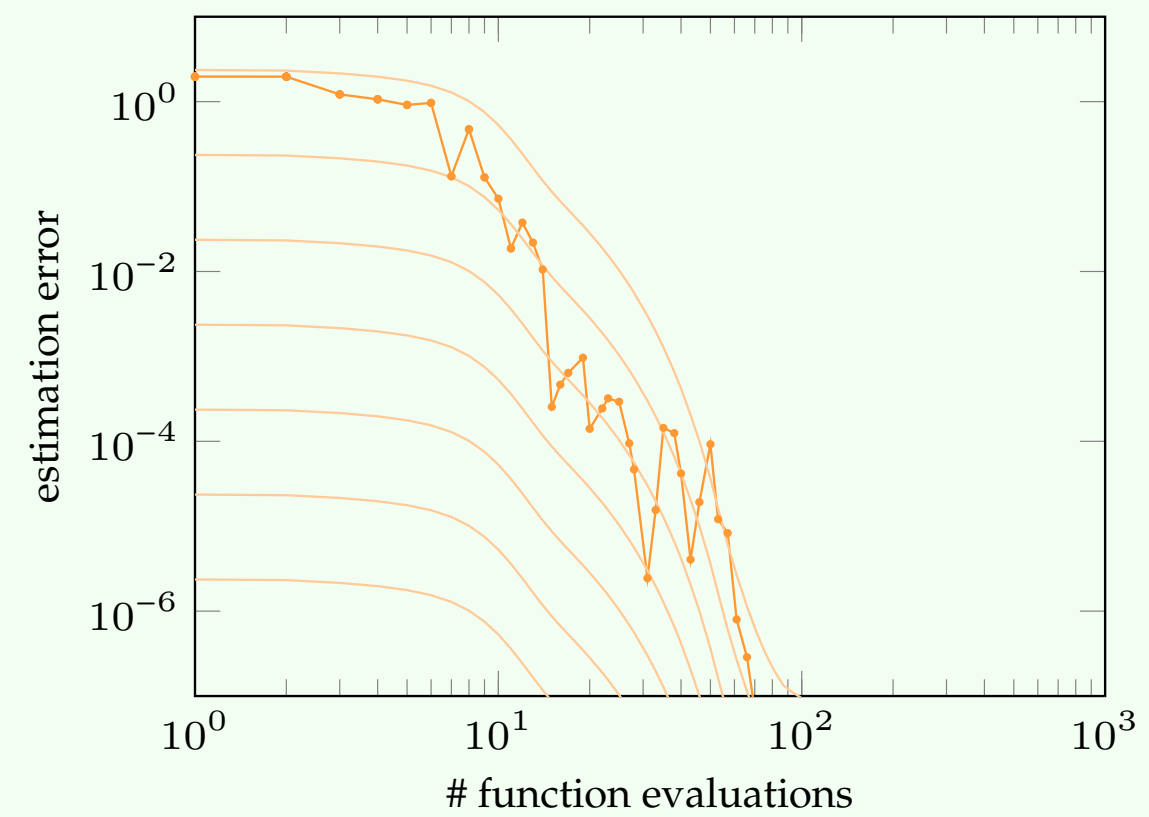
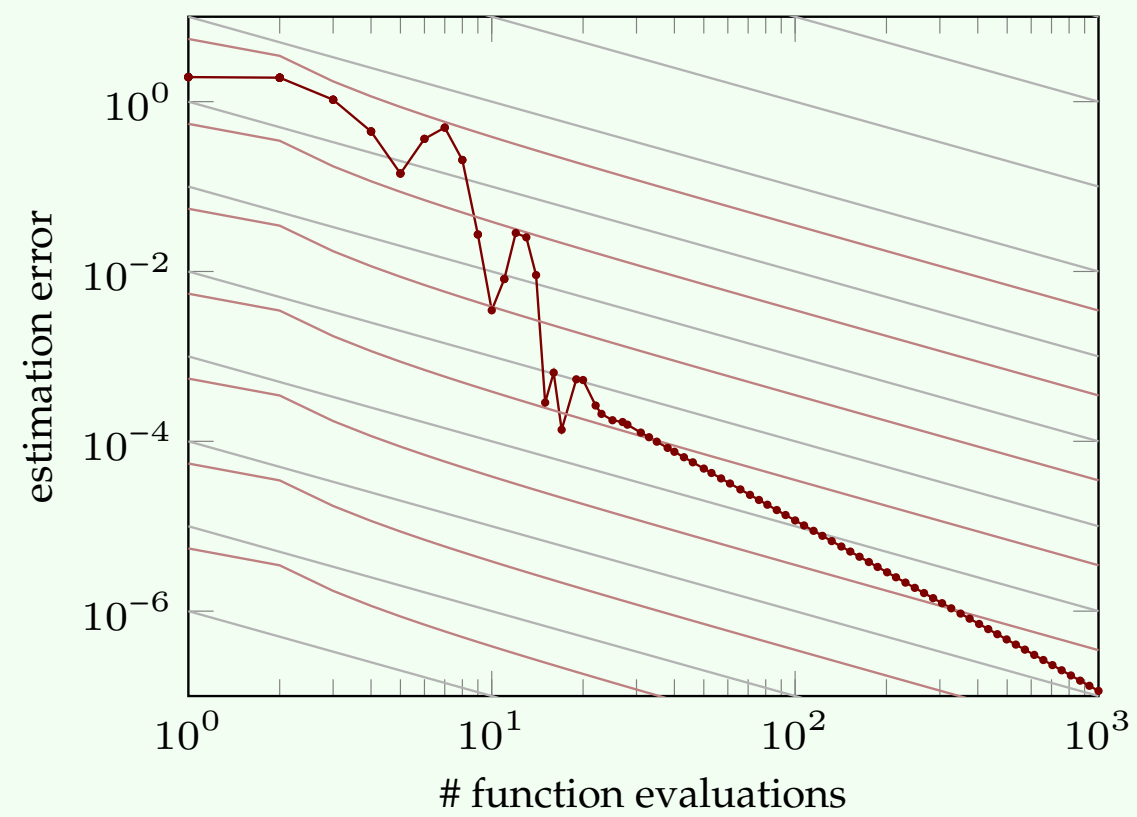
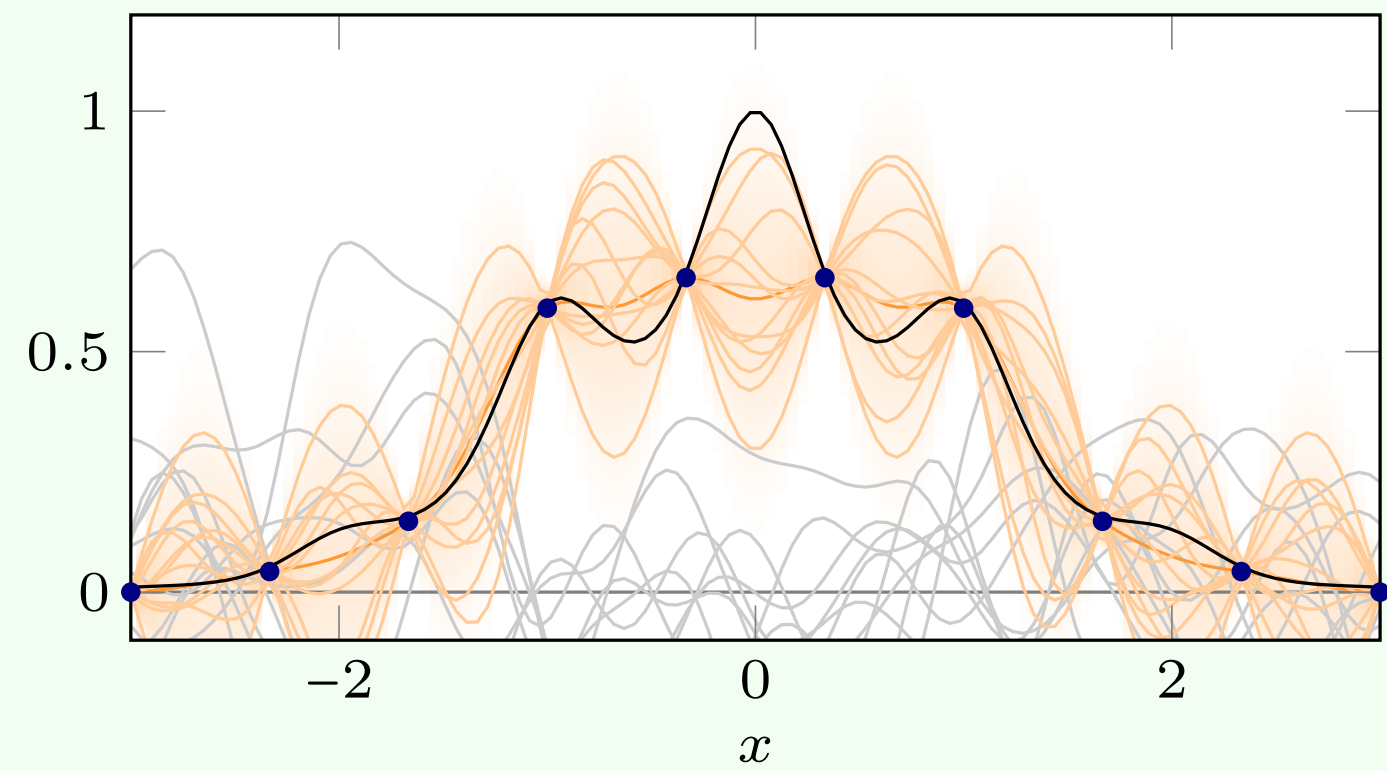
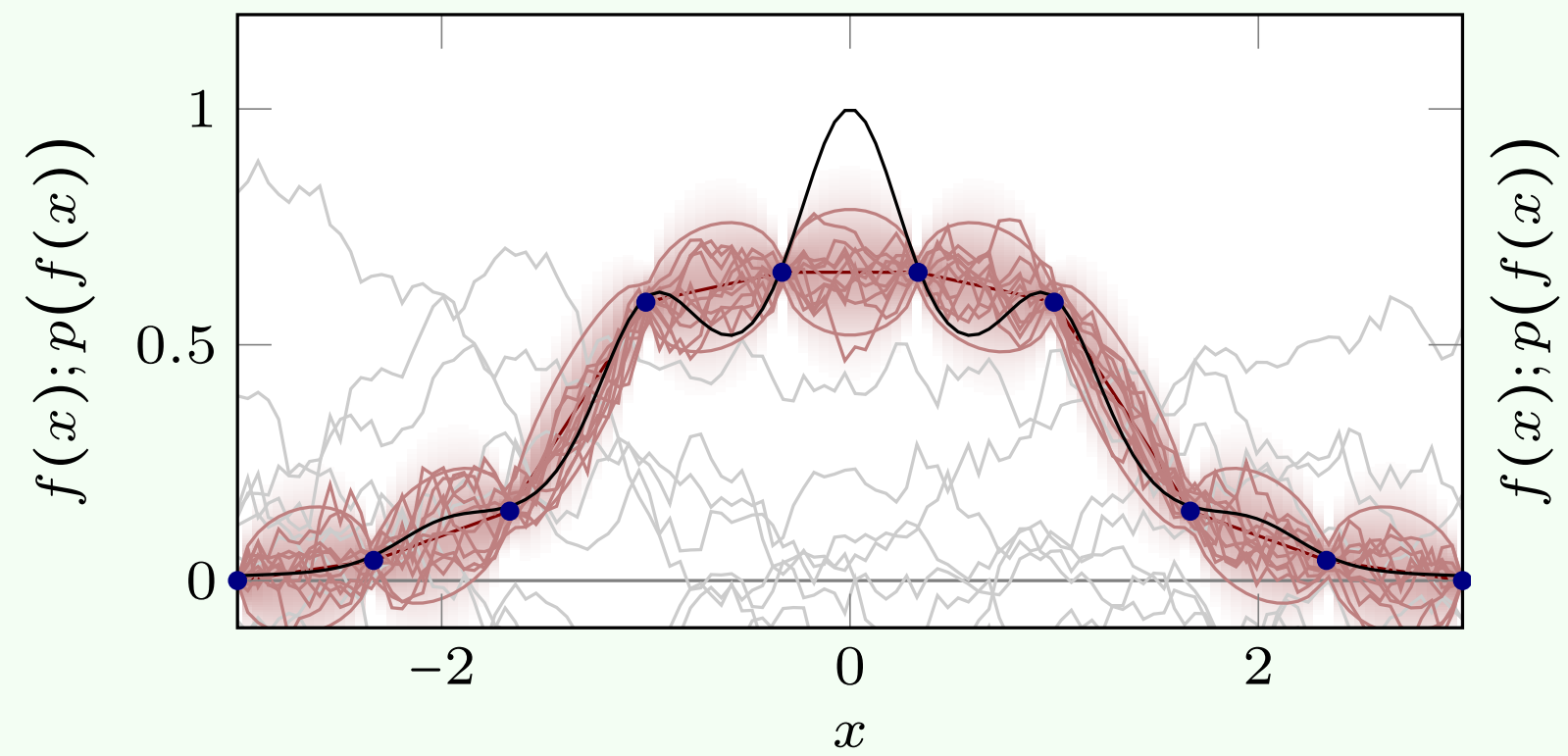
for arbitrary $\theta \in \mathfrak{R}_+$ and $\chi < a \in \mathfrak{R}$.



```
1 procedure INTEGRATE(@f, a, b, N,  $\theta$ )
2    $\delta := (b - a) / (N - 1)$                                 // choose step size
3    $x \leftarrow a, y_1 = f(a), m \leftarrow 0, v \leftarrow 0,$       // initialise
4   for  $i = 2, \dots, N$  do
5      $x \leftarrow x + \delta$                                     // step
6      $y_i \leftarrow f(x)$                                        // evaluate
7      $m \leftarrow m + \delta/2(y_{i-1} + y_i)$                   // update estimate
8      $v \leftarrow v + \delta^3/12$                                 // update error estimate
9   end for
10  return  $\mathbb{E}(F) = m, \text{var}(F) = \theta^2 v$                 // probabilistic output
11 end procedure
```

```
1 procedure INTEGRATE(@f, a, b, N,  $\theta$ )
2    $\delta := (b - a) / (N - 1)$  // choose step size
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6      $y_i \leftarrow f(x)$  // evaluate
7      $m \leftarrow m + \delta / 2 (y_{i-1} + y_i)$  // update estimate
8      $v \leftarrow v + \delta^3 / 12$  // update error estimate
9   end for
10  return  $\mathbb{E}(F) = m, \text{var}(F) = \theta^2 v$  // probabilistic output
11 end procedure
```

The trapezoid rule *is* Bayesian quadrature.



Quiz: The convergence rate of the trapezoid rule is $\mathcal{O}(N^{-1})$: what is the rate of **Monte Carlo**?

1. $\mathcal{O}(\exp(-N))$
2. $\mathcal{O}\left(\exp\left(-N^{-\frac{1}{2}}\right)\right)$
3. $\mathcal{O}(N^{-1})$
4. $\mathcal{O}\left(N^{-\frac{1}{2}}\right)$

Quiz: The convergence rate of the trapezoid rule is $\mathcal{O}(N^{-1})$: what is the rate of **Monte Carlo**?

1. $\mathcal{O}(\exp(-N))$

2. $\mathcal{O}\left(\exp\left(-N^{-\frac{1}{2}}\right)\right)$

3. $\mathcal{O}(N^{-1})$

4. $\mathcal{O}(N^{-\frac{1}{2}})$ – **arguably the worst possible rate.**

Monte Carlo **is also** Bayesian quadrature.

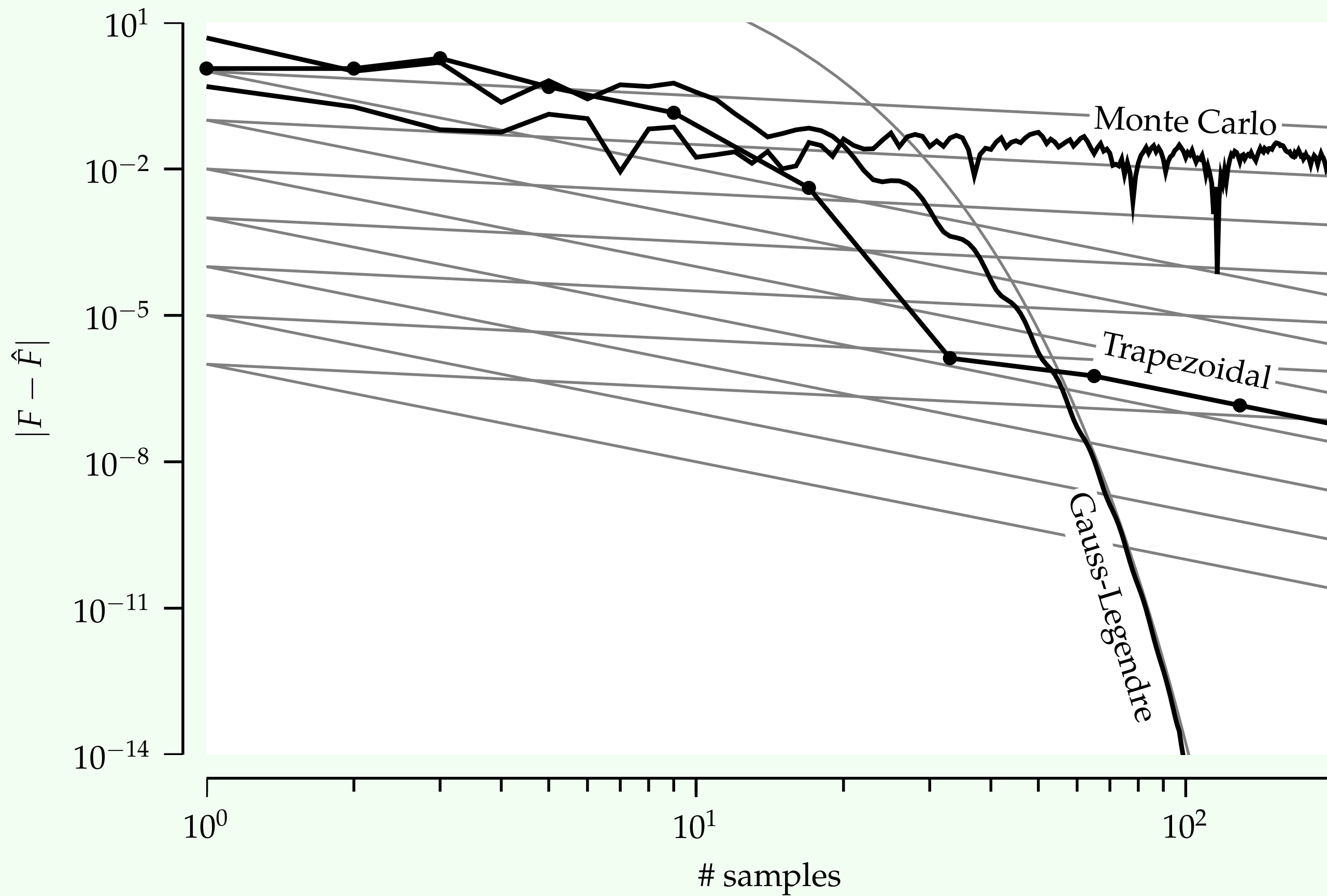
The Monte Carlo estimate

$$\int f(x) p(x) \mathrm{d}x \simeq \frac{1}{N} \sum_{i=1}^N f(x_i)$$

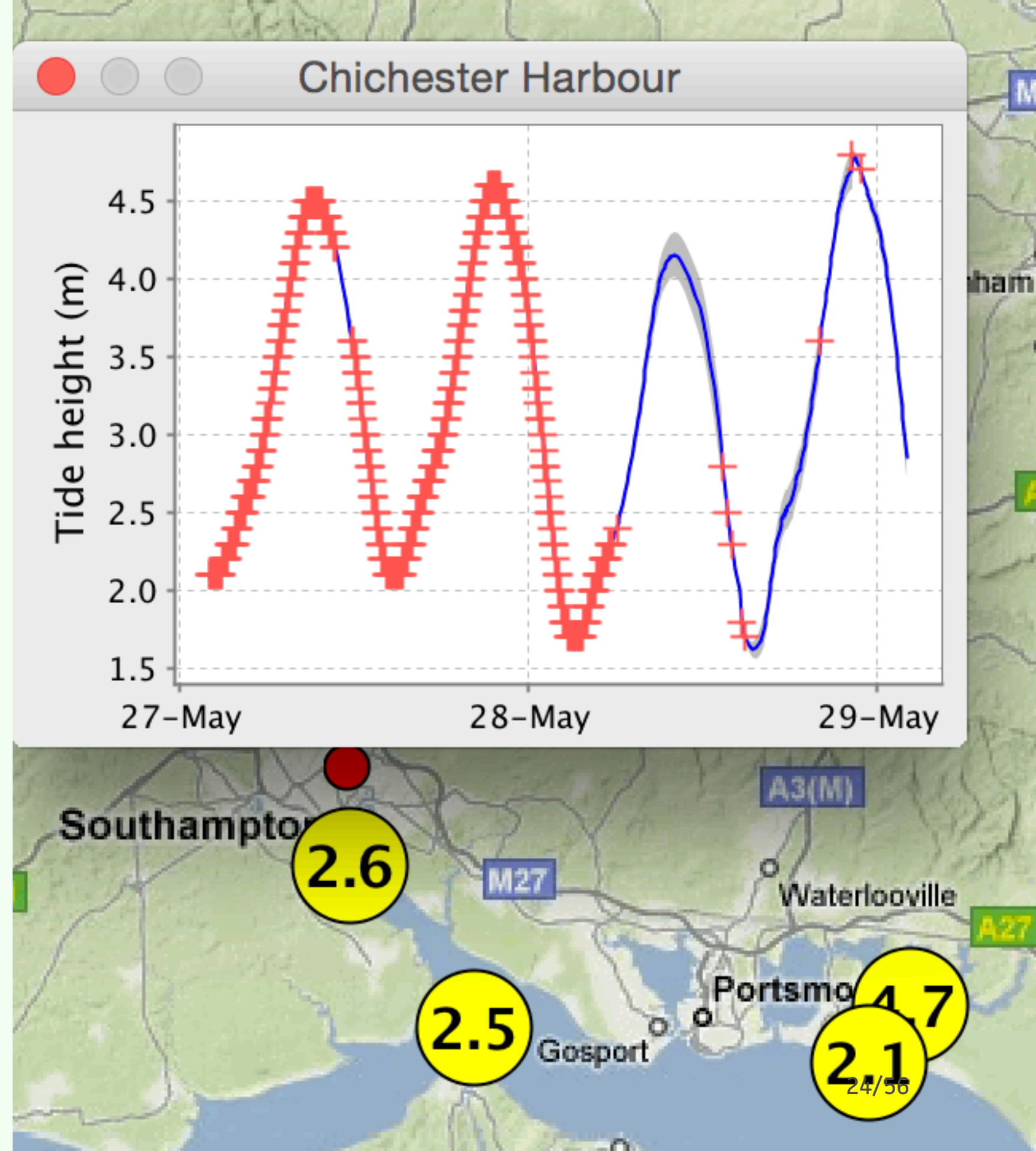
is maximum a-posteriori under the (improper) prior

$$p(f) = \lim_{c \rightarrow 0} \mathcal{GP}(0, \theta^2 \mathbb{I}(x = x') + c^{-1})$$

for \mathbb{I} the indicator function and with arbitrary $\theta \in \mathfrak{R}_+$. The corresponding posterior standard deviation estimate on the integral, $\theta(b-a)/\sqrt{N}$, matches the convergence rate of the Monte Carlo estimator.

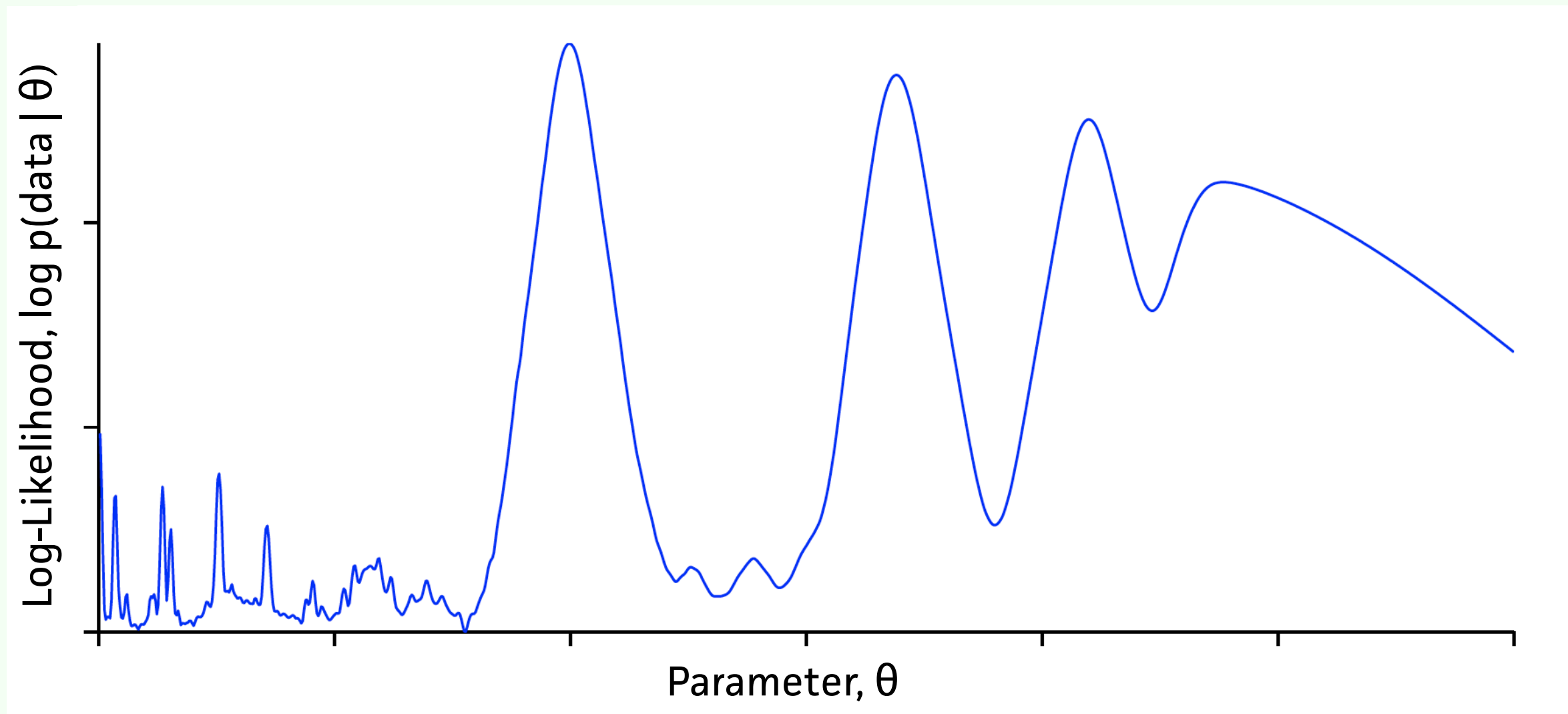


Quadrature is
often required to
manage model
parameters.



Managing parameters θ requires the **model evidence**,

$$p(\text{data}) = \int p(\text{data} \mid \theta) p(\theta) d\theta.$$



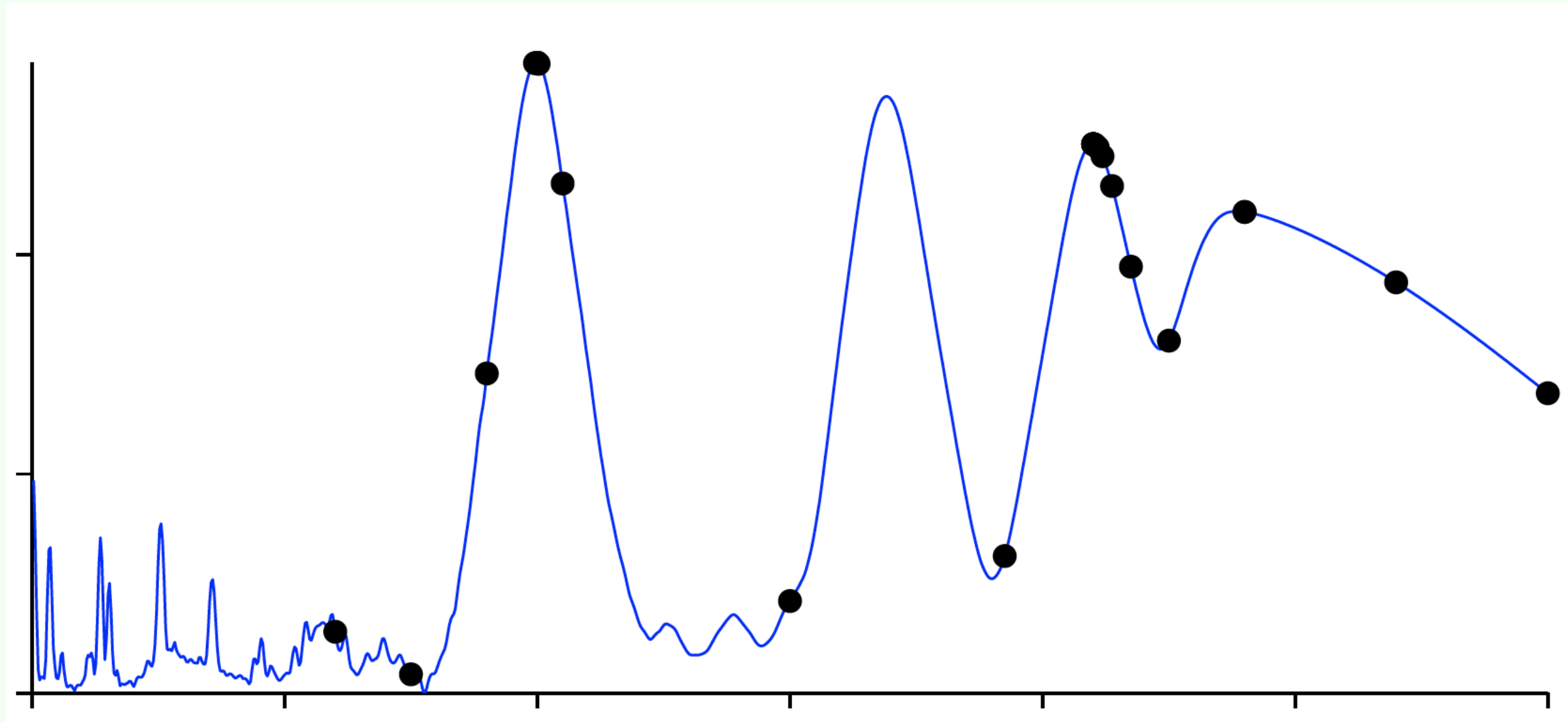


QUADRATURE

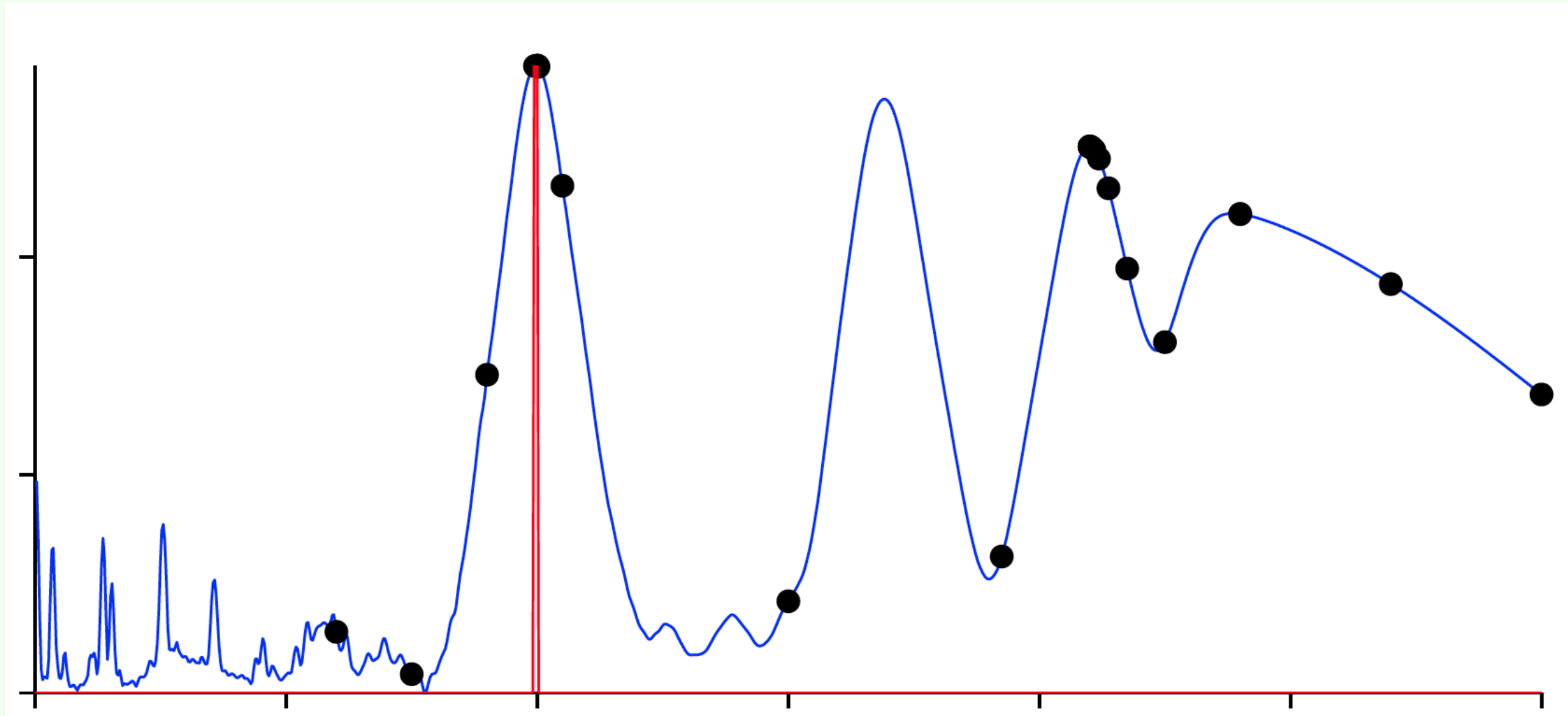
IS HARD.

Parameter, θ

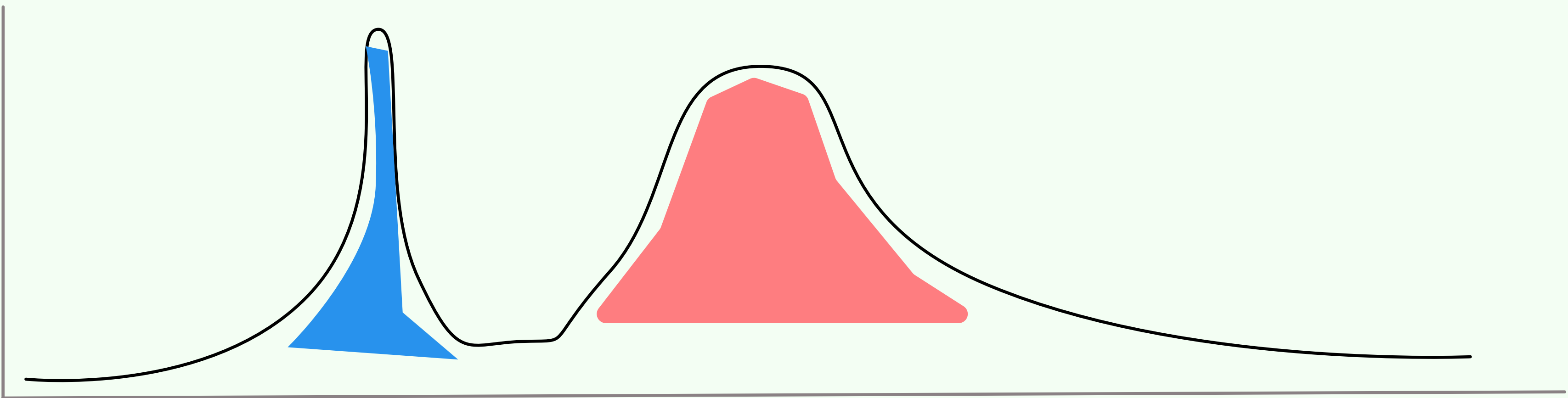
Optimisation (maximum likelihood, training) is often used in the place of quadrature.



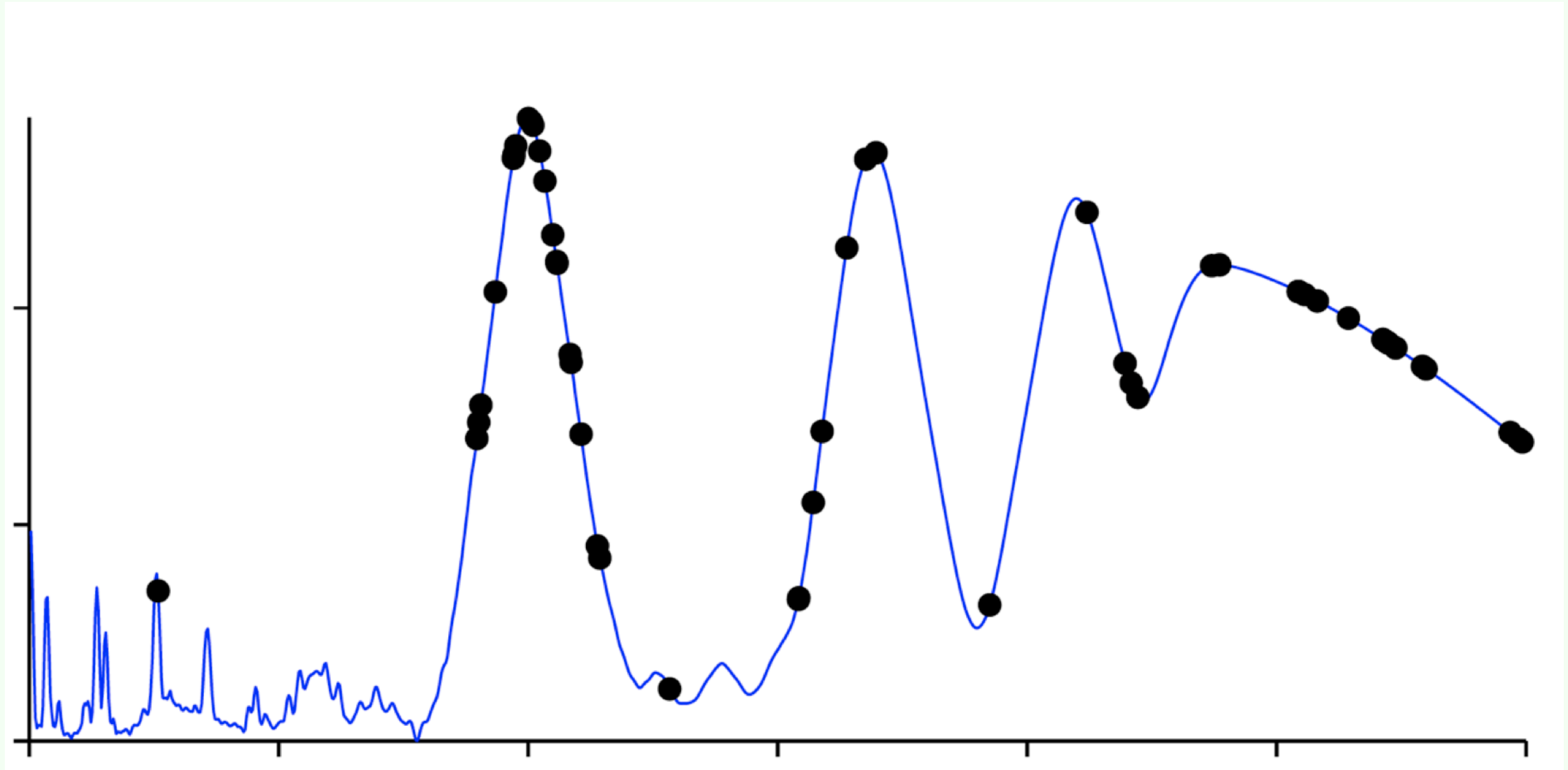
This approximates as $p(\text{data}) \simeq \int p(\text{data} \mid \theta) \delta(\theta - \theta_{\text{max}}) d\theta$.



If optimising, **flat optima** are often a better representation of the integral than **narrow optima**.

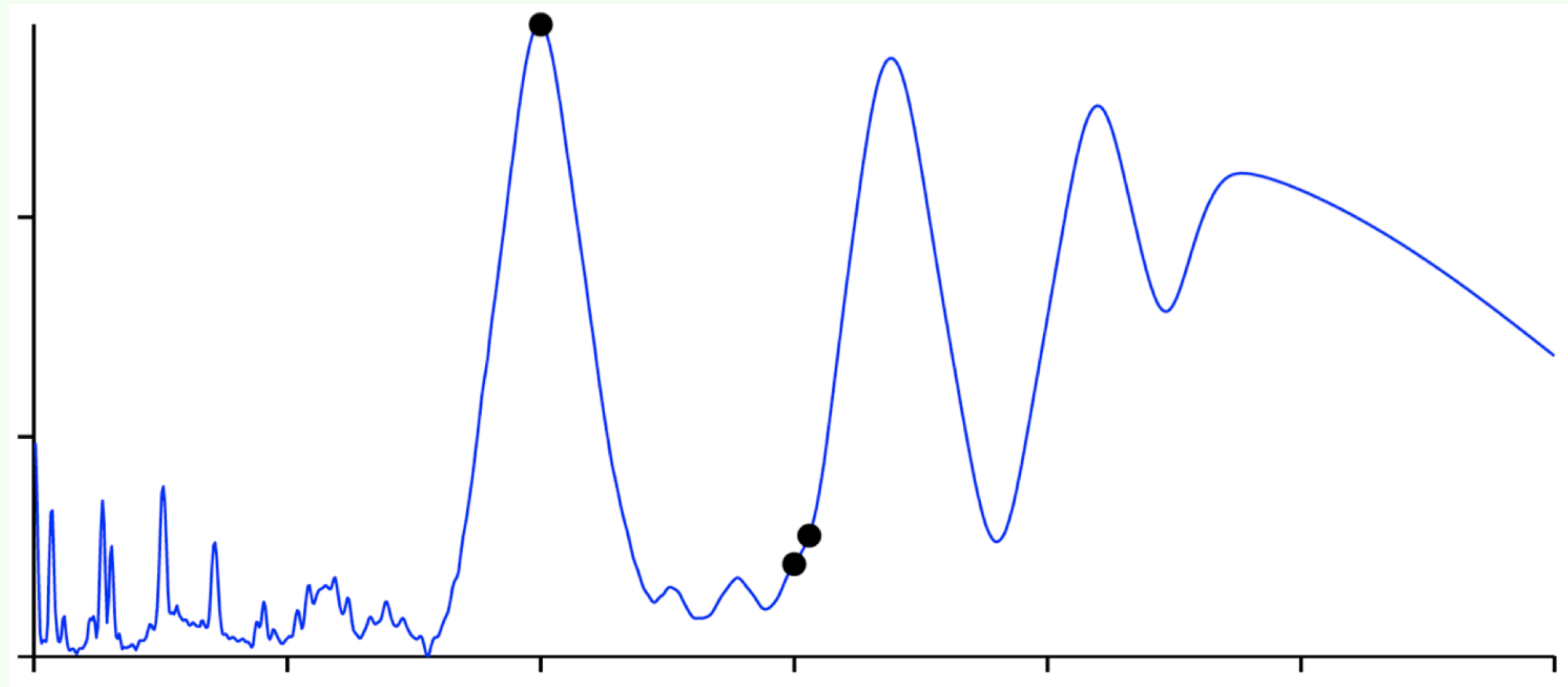


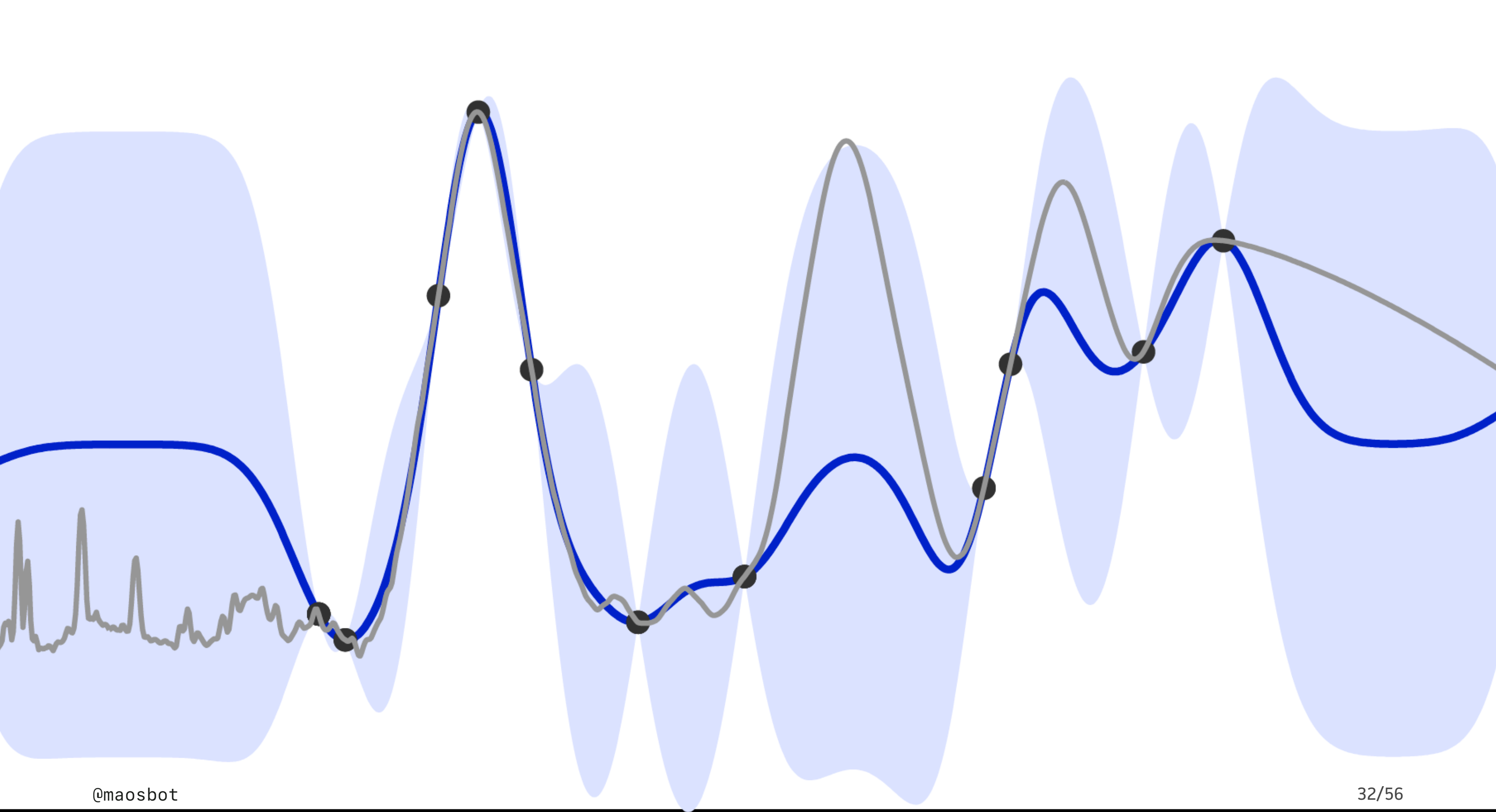
Monte Carlo has revolutionised Bayesian inference.



Monte Carlo estimators, $\int f(x) p(x) dx \simeq \frac{1}{N} \sum_{i=1}^N f(x_i)$,

ignore relevant information.





```
ea = params[1]
```

```
wa = params[2:3]
```

```
secw, sesw = np.sqrt(ea)*np.cos(wa), np.sqrt(ea)*np.sin(wa)
```

We often have relevant prior knowledge: like the problem's source code.

```
bx, by = af.baseline_m(df.time, pv_base, df.px, df.py, nthr)
```

```
px, py = af.am_model_em(df.time, np.r_[pv_base, pv_1, pv_2], 2, 1)
```

```
mx, my = 1e6*(bx+px), 1e6*(by+py)
```

```
ea = params[0]
```

```
wa = params[2:3]
```

```
secw, sesw = np.sqrt(ea)*np.cos(wa), np.sqrt(ea)*np.sin(wa)
```

The perfect prior
is intractable.


```
pv_1 = np.array([6.2, -7.26, secw[0], sesw[0], 1.1, 1.21, 0.80])
```

```
pv_2 = np.array([5.5, -8.23, secw[1], sesw[1], 2.3, 0.79, 1.38])
```

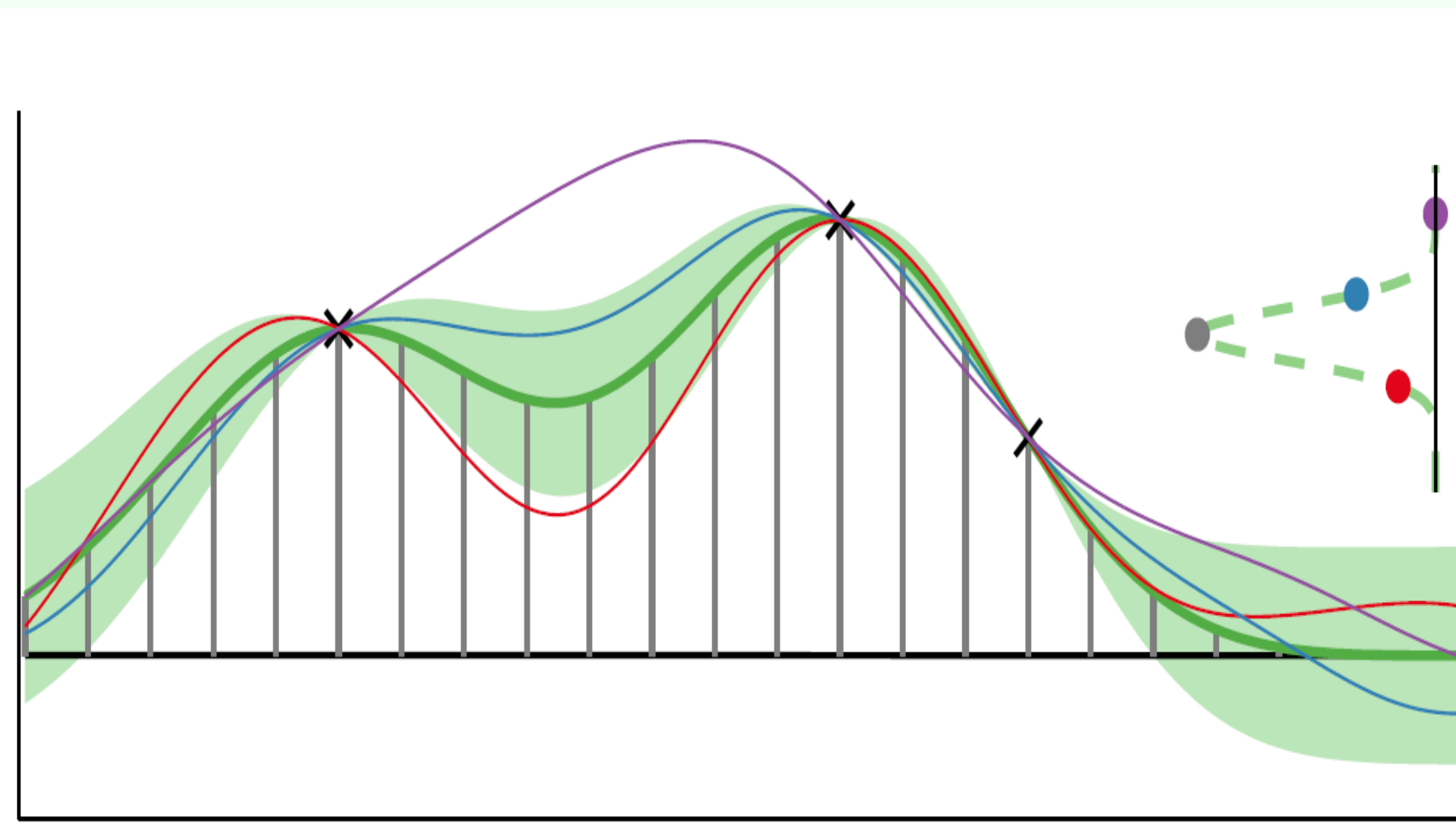
```
bx, by = af.baseline_m(df.time, pv_base, df.px, df.py, nthr)
```

```
px, py = af.am_model_em(df.time, np.r_[pv_base, pv_1, pv_2], 2, 1)
```

```
mx, my = 1e6*(bx+px), 1e6*(by+py)
```

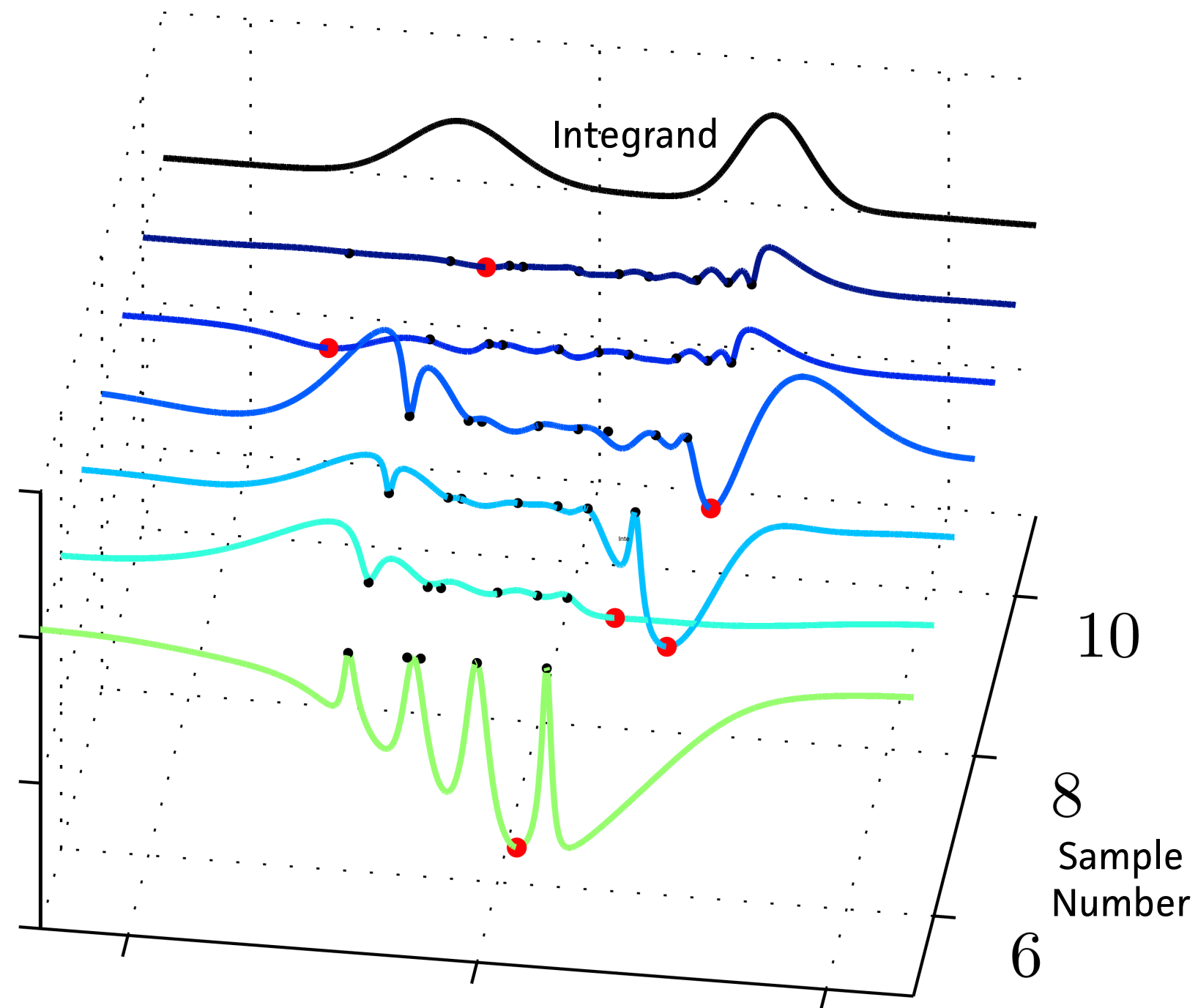



**An agent is defined by
its prior and
loss function.**

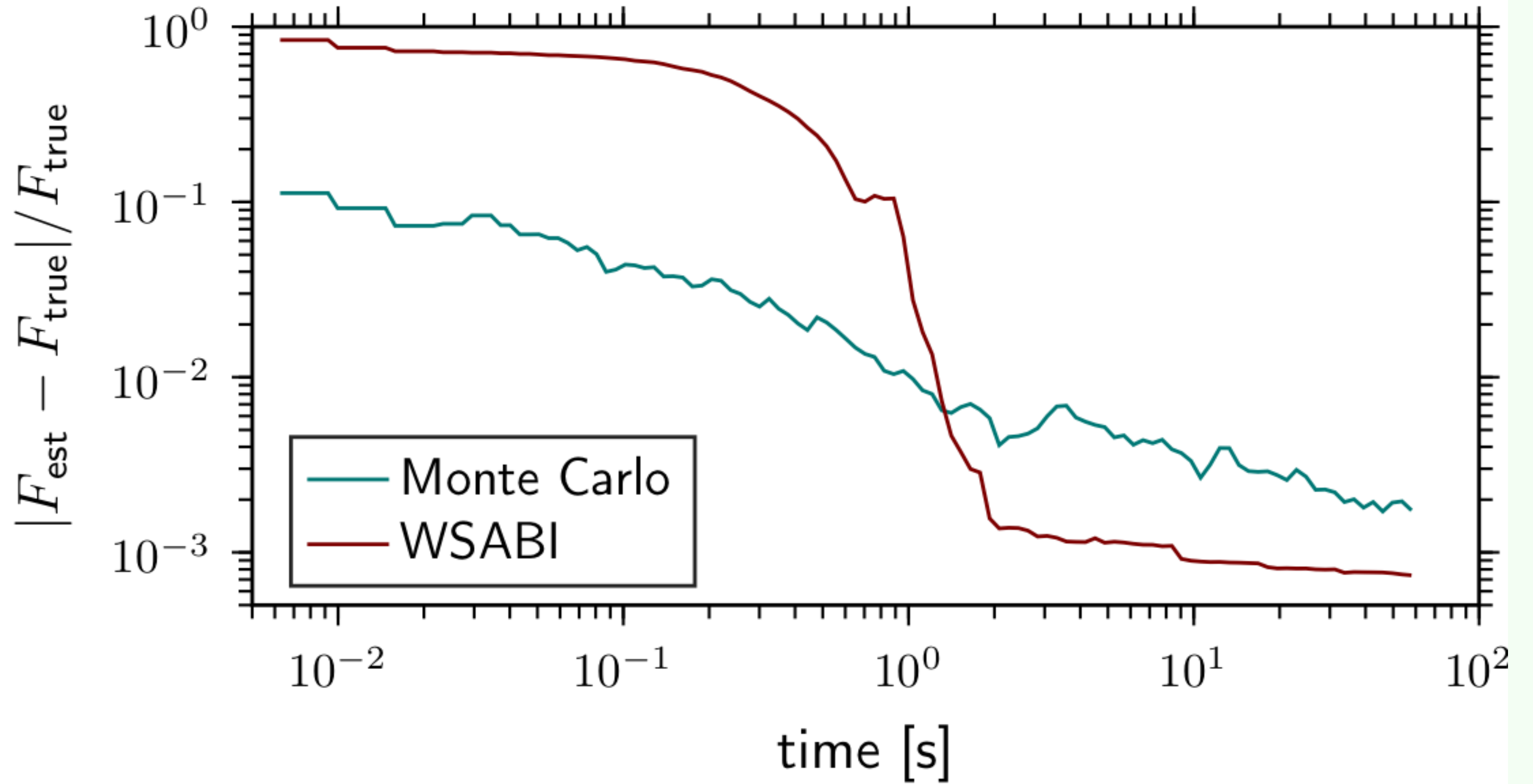


A natural **loss function** for quadrature is the **uncertainty in the integral**.

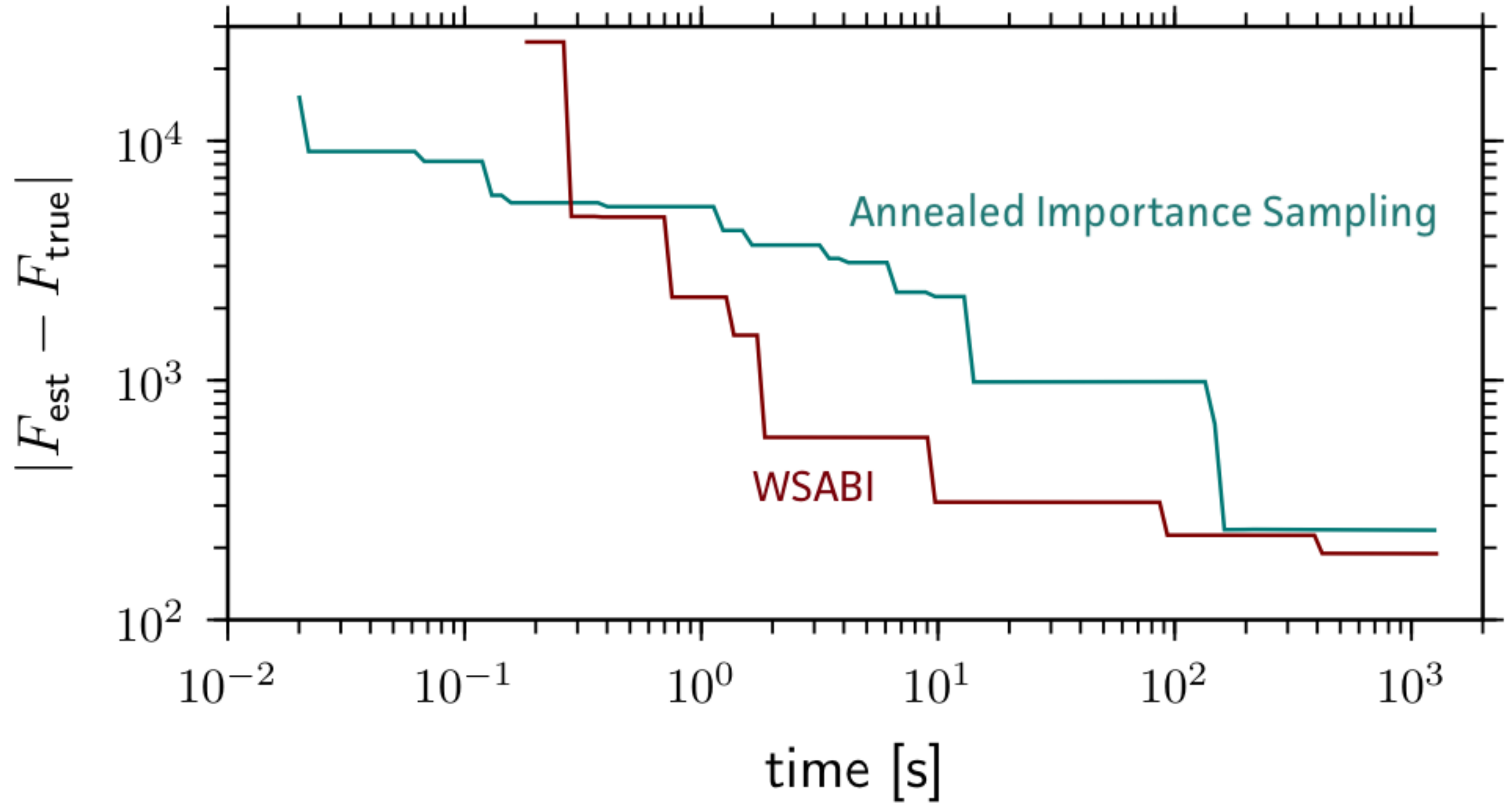
WSABI uses a loss that is the uncertainty in the integrand.



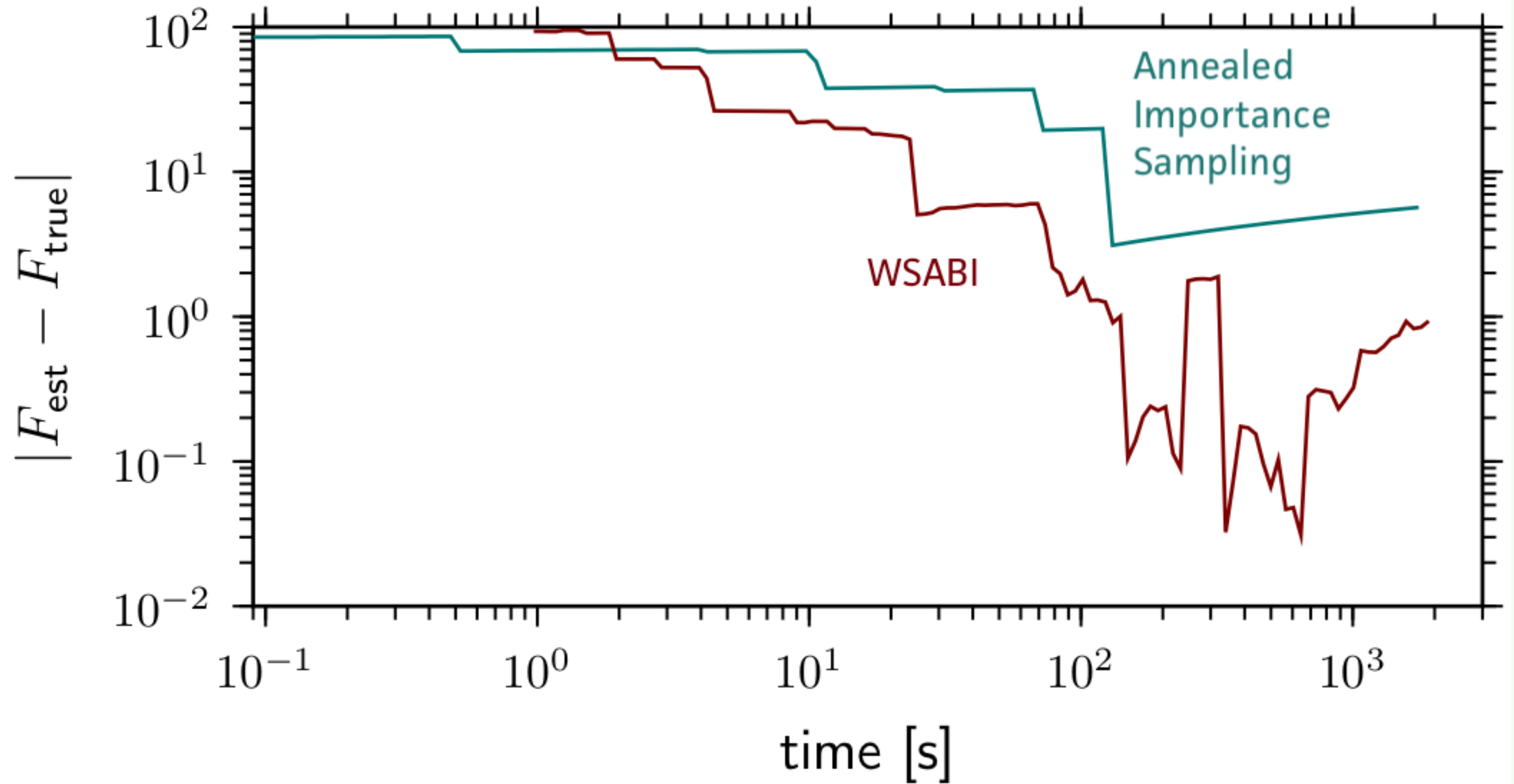
synthetic (moG)



yacht hydrodynamics



GP classification, graph



Overhead
can set you
free.

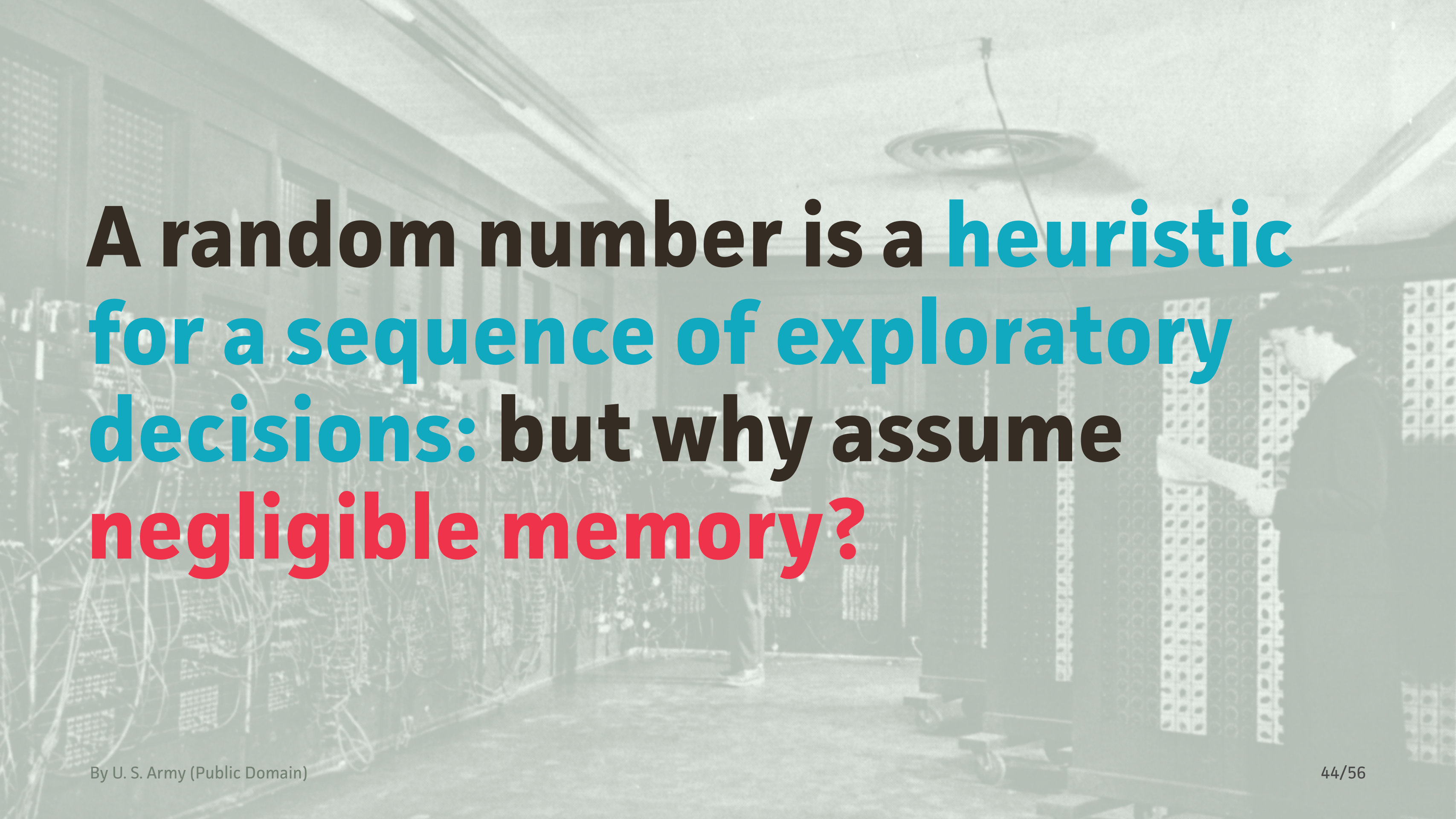
By Paulhaberstroh [CC BY-SA 4.0], from Wikimedia Commons



**A RANDOM
NUMBER IS
A DECISION.**



**A random number assumes a
completely flat expected loss.**

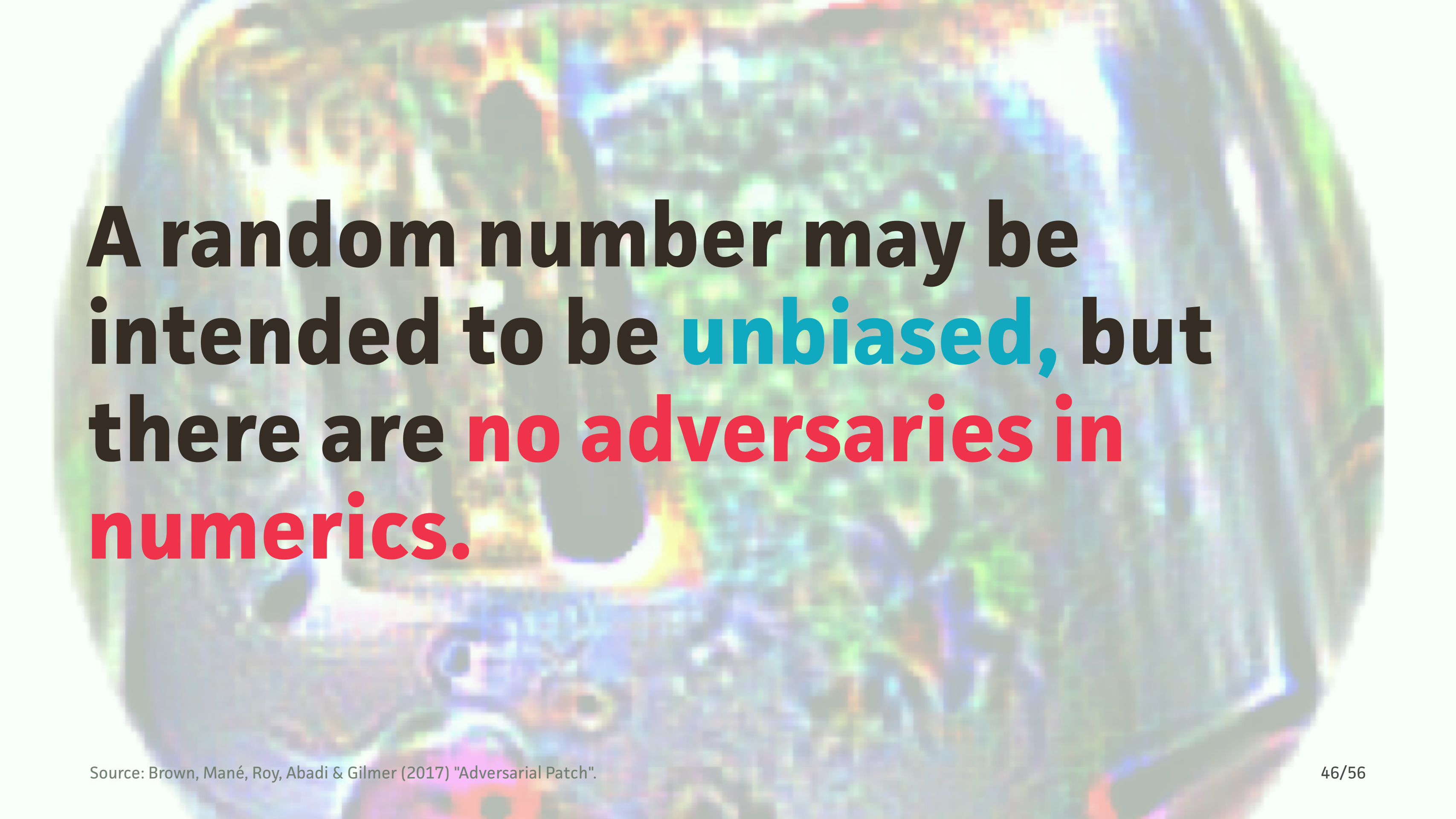
A grayscale photograph of a large, early computer system, likely the ENIAC. The machine consists of numerous tall, vertical panels or cabinets filled with electronic components. A person is standing to the right of the machine, looking at one of the panels. The room has a high ceiling with a circular light fixture. The text is overlaid on the image in a large, bold font with different colors for emphasis.

**A random number is a heuristic
for a sequence of exploratory
decisions: but why assume
negligible memory?**



Using random numbers makes your algorithm **unimprovable**.

Source: By Jake Archibald from London, England - Sebastian Vettel - Ferrari - Halo, [CC BY 2.0](#). References: Henderson et al. “Deep Reinforcement Learning that Matters” (2017); Islam et al. “Reproducibility of Benchmarked Deep Reinforcement Learning Tasks for Continuous Control” (2017); Colas, Sigaud, and Oudeyer. “How Many Random Seeds? Statistical Power Analysis in Deep Reinforcement Learning Experiments” (2018); Mania, Guy, and Recht. “Simple random search provides a competitive approach to reinforcement learning” (2018).



A random number may be intended to be unbiased, but there are no adversaries in numerics.

Quiz: which of these sequences is **random**?

1. 622444111111114444443333333
2. 1693993751058209749445923078
3. 7129042634726105902083360448
4. 100011111011111111001010000

Quiz: which of these sequences is **random**?

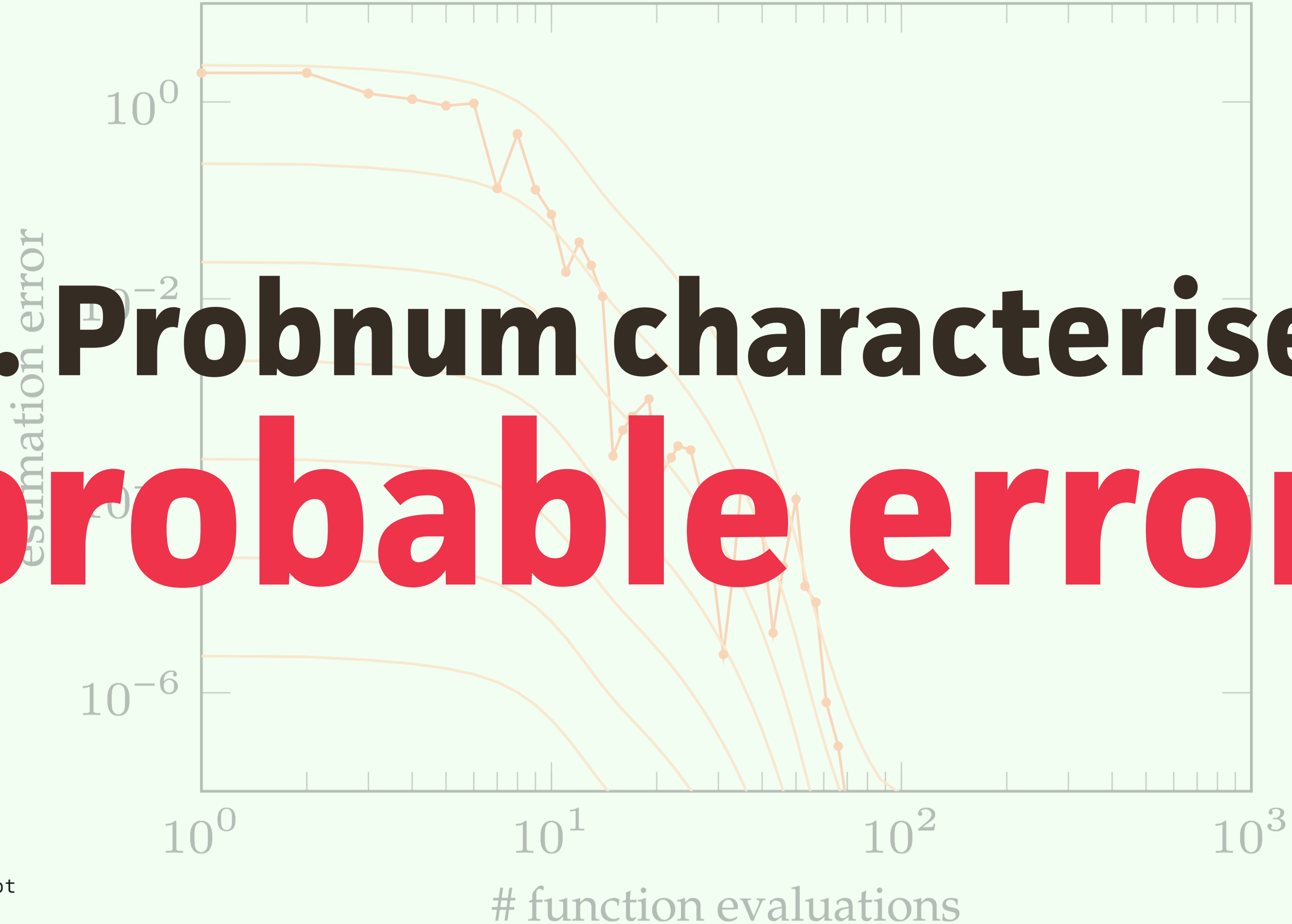
1. 622444111111114444443333333: seven d6 rolls with i repeats of the i th roll.
2. 1693993751058209749445923078: the 41st to 70th digits of π .
3. 7129042634726105902083360448: this sequence was generated by the von Neumann method with seed 908344.
4. 1000111111011111111001010000: digits taken from a CD-ROM published by George Marsaglia.

A finite string of random numbers is **encoding some bias!**

Recall:

- 1. numeric **error** is significant;**
- 2. numeric methods are **generic**;**
- 3. our numerics problems **tax**
our computation.**

1. Probnun characterises probable error.




```
17 class Robot_base():
```

```
18 def __init__(self):
```

```
19     self.name = 'Robot_jit_arm_Simulation'
```

```
20     self.os_type = platform.system()
```

```
21
```

```
22 def __init__(self, args):
```

```
23     self.jt_angle = 1, 'jt_angle is being dimensional'
```

```
24     assert len(jt_angle) == 3, 'jt_angle has to have 3 inputs'
```

```
25
```

```
26 if self.os_type == "Linux":
```

```
27     args = str('./robot_arm.py') + str(jt_angle)
```

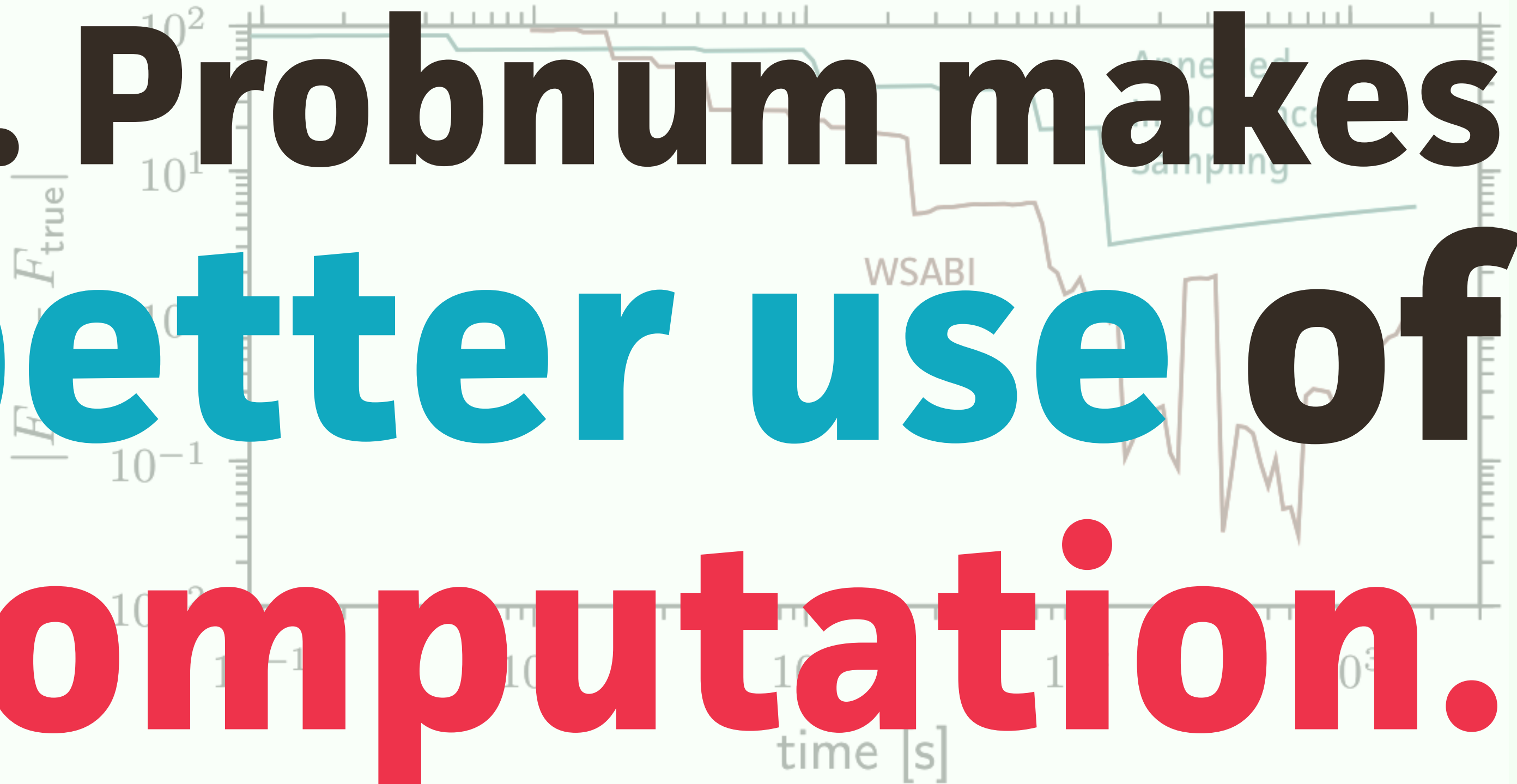
```
28     proc = subprocess.Popen(args, shell=True, stdout=subprocess.PIPE)
```

```
29 if self.os_type == "Windows":
```

```
30     args = str('robot_arm.exe') + str(jt_angle[0]) + ' ' + str(jt_ang
```

```
31     proc = subprocess.Popen(args, stdout=subprocess.PIPE)
```

3. Probbnum makes
better use of
computation.





PROBABILISTIC-NUMERICS.ORG

Numerical algorithms, such as methods for the numerical solution of differential equations, as well as optimization algorithms. They estimate the value of a latent, intractable quantity, such as the value of a differential equation, the location of an extremum,

probnum.org

Numerical algorithms, such as methods for the numerical solution of ordinary differential equations, as well as optimization algorithms, are used to estimate the value of a latent, intractable quantity.

of a differential equation, the location of an extremum

LITERATURE

This page collects literature on all areas of probability and numerical analysis. If you have a paper that is not yet in the bibliography, do not hesitate to contact us. The fastest way to get a paper added is to send us a pull-request to the file in `/_bibliography`, then either send us a pull-request or a link to the paper.

QUICK-JUMP LINKS:

- [General and Foundational](#)
- [Quadrature](#)
- [Linear Algebra](#)
- [Optimization](#)
- [Ordinary Differential Equations](#)
- [Partial Differential Equations](#)



Huge thanks to
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Hennig.