



Department of Mathematical Sciences

Causal Inference in Dynamical Systems

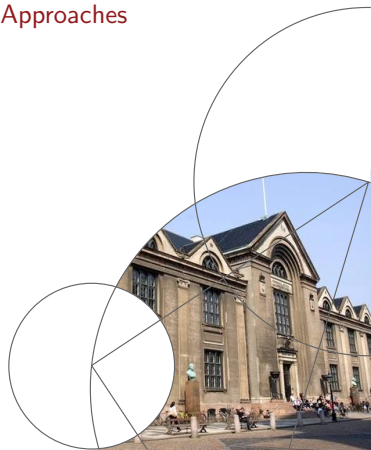
Convergent Cross Mapping and Alternative Approaches

Master's Defense

Rasmus Juhl Christensen
stud.scient.

January 15th, 2024

Slide 1/14



Program

10.30-11.00: A presentation on the following topics:

- ① Time Series
- ② Stochastic Models
- ③ Granger Causality
- ④ Dynamical Models
- ⑤ Takens' Theorem
- ⑥ Convergent Cross Mapping
- ⑦ Extensions

11.00: Questions.

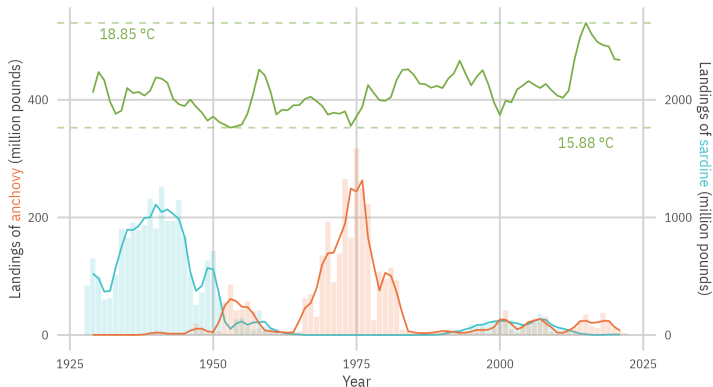


Time Series

Consider the following example:

Sardine and Anchovy Landings

The yearly and 3-year averages of landings of **sardine** and **anchovy** compared with 3-year averages of **sea surface temperature** from 1928-2022 in the California Current System.



Source: Calif. Dept. of Wildlife and Game



Time Series Characteristics

We imagine the following generical set-up in this presentation:

$$X_1, \dots, X_T$$

$$Y_1, \dots, Y_T$$

$$Z_1, \dots, Z_T$$

We consider thus the following features of our models:



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→ identifiability from lagged information.



Stochastic Models

We get the randomness in stochastic models via noise terms. For each variable, we will model as follows:

$$X_t = f(\underbrace{X_{t-1}}_{\text{last state}}, \underbrace{\dots\dots\dots}_{\text{additional information}}, \underbrace{u_t^X}_{\text{noise}})$$



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- „Changes in the cause will result in changes in the effect“.



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- Reformulated in terms of Granger causality:

$$X_t \not\perp\!\!\!\perp Z_{t-1} \mid (X_{t-1}, Y_{t-1})$$



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Causality:

- „Changes in the cause will result in changes in the effect“.
- In this example: Z *causes* X and Y .
- How do we detect it?



Chaotic Attractors

Meteorologist Edward Lorenz at MIT modelled atmospheric convection, and discovered the Lorenz system in 1963:

$$\begin{aligned}\frac{dX_t}{dt} &= \sigma(Y_t - X_t), & \frac{dY_t}{dt} &= -X_t Z_t + rX_t - Y_t, \\ \frac{dZ_t}{dt} &= X_t Y_t - bZ_t\end{aligned}$$

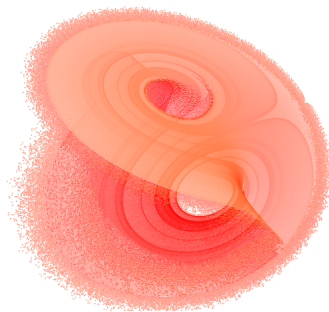


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Result: a butterfly!



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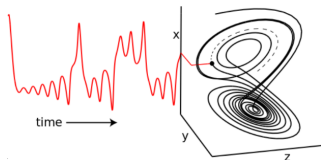


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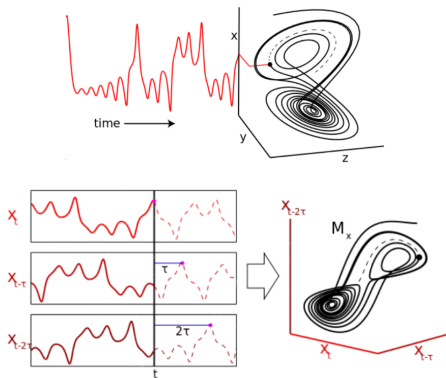


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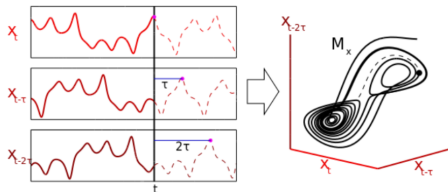
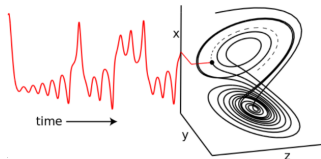


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Slide 8/14

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Takens' theorem:

$$(X_t, Y_t, Z_t) \mapsto (X_t, X_{t-\tau}, \dots, X_{t-4\tau})$$

is an *embedding* of the attractor *generically*. In particular,



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Key ingredients:

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- Emergence of geometric structure from solutions.
- Decomposition of geometry according to causal structure.



Convergent Cross Mapping

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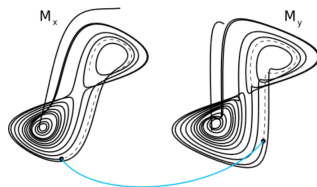
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We compute the cross-mapping skill as the correlation between $\hat{Y}_t | M_X$ and Y_t .



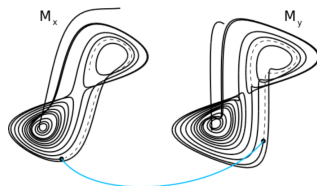
Convergent Cross Mapping pt. 2

Visualization:

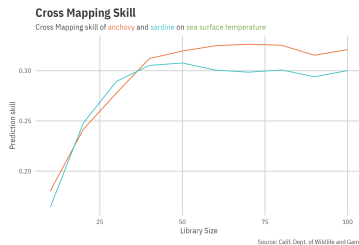
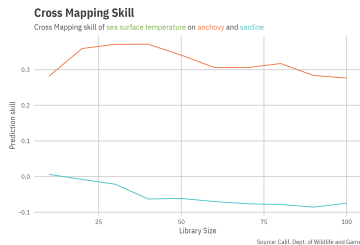


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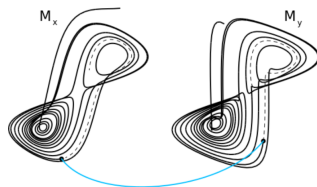


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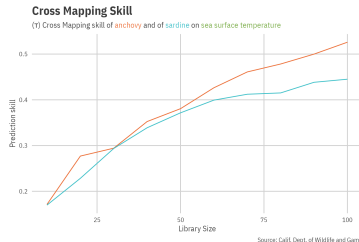
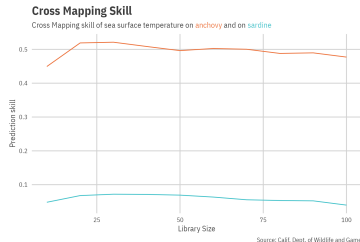


Convergent Cross Mapping pt. 2

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In practice (no transformation!) with $\tau = 2$, $E = 4$:



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- Regime dependence.



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- 3 We can imagine

$$\frac{dX_t}{dt} = f(X_t, X_{t-\tau}, Y_t, \dots)$$



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- 1 Give a full description of a model satisfying the theoretical guarantees.
- 2 We can imagine that we observe

$$X_t + \varepsilon_t^X$$

with some observation noise X_t .

- 3 We can imagine

$$\frac{dX_t}{dt} = f(X_t, X_{t-\tau}, Y_t, \dots)$$

- 4 Alternative, we can imagine an SDE

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- 5 The link between limiting distributions and attractor sets.



Questions

