

# Interpolation of Molecular Dynamics Trajectories with Bi-Directional Neural Networks

Ludwig Winkler & Huziel Saucedo

November 30, 2020

# Molecular Dynamics (MD)

- "Classical" dynamics of molecules are governed by Newton's equations of motion

# Molecular Dynamics (MD)

- "Classical" dynamics of molecules are governed by Newton's equations of motion
- Position  $r(t)$  and momentum  $p(t)$  describe the system completely

# Molecular Dynamics (MD)

- "Classical" dynamics of molecules are governed by Newton's equations of motion
- Position  $r(t)$  and momentum  $p(t)$  describe the system completely
- Dynamics  $f$  given by differential equation

$$\dot{x}(t) = \begin{bmatrix} \dot{r}(t) \\ \dot{p}(t) \end{bmatrix} = f \left( \begin{bmatrix} r(t) \\ p(t) \end{bmatrix}, t \right)$$

# Molecular Dynamics (MD)

- "Classical" dynamics of molecules are governed by Newton's equations of motion
- Position  $r(t)$  and momentum  $p(t)$  describe the system completely
- Dynamics  $f$  given by differential equation

$$\dot{x}(t) = \begin{bmatrix} \dot{r}(t) \\ \dot{p}(t) \end{bmatrix} = f \left( \begin{bmatrix} r(t) \\ p(t) \end{bmatrix}, t \right)$$

- Solution is a trajectory in phase space

$$x(t) = \begin{bmatrix} r(t) \\ p(t) \end{bmatrix} = \int_{t_0}^t f \left( \begin{bmatrix} r(t) \\ p(t) \end{bmatrix}, t \right) dt$$

# Molecular Dynamics (MD)

- High accuracy description of high dimensional N-bodies are expensive to compute

# Molecular Dynamics (MD)

- High accuracy description of high dimensional N-bodies are expensive to compute
- MD requirements for a statistical meaningful result
  - $\Delta t = 0.2 \text{ fs}$  time step size for accurate integration of the equations of motion
  - $T \sim 1 \text{ ns}$ :  $10^6 - 10^7$  integration steps for expressive properties

# Molecular Dynamics (MD)

- High accuracy description of high dimensional N-bodies are expensive to compute
- MD requirements for a statistical meaningful result
  - $\Delta t = 0.2 \text{ fs}$  time step size for accurate integration of the equations of motion
  - $T \sim 1 \text{ ns}$ :  $10^6 - 10^7$  integration steps for expressive properties
- Dynamics  $f$  are expensive to solve for long simulations



# Molecular Dynamics (MD)

- High accuracy description of high dimensional N-bodies are expensive to compute
- MD requirements for a statistical meaningful result
  - $\Delta t = 0.2 \text{ fs}$  time step size for accurate integration of the equations of motion
  - $T \sim 1 \text{ ns}$ :  $10^6 - 10^7$  integration steps for expressive properties
- Dynamics  $f$  are expensive to solve for long simulations
- Single Thread DFT:  $10s$  integration step requires 110 days

# Molecular Dynamics (MD)

- High accuracy description of high dimensional N-bodies are expensive to compute
- MD requirements for a statistical meaningful result
  - $\Delta t = 0.2 \text{ fs}$  time step size for accurate integration of the equations of motion
  - $T \sim 1 \text{ ns}$ :  $10^6 - 10^7$  integration steps for expressive properties
- Dynamics  $f$  are expensive to solve for long simulations
- Single Thread DFT:  $10s$  integration step requires 110 days
- Yet, essentially we are dealing with a time series prediction problem ...

# Molecular Dynamics (MD)

- High accuracy description of high dimensional N-bodies are expensive to compute
- MD requirements for a statistical meaningful result
  - $\Delta t = 0.2 \text{ fs}$  time step size for accurate integration of the equations of motion
  - $T \sim 1 \text{ ns}$ :  $10^6 - 10^7$  integration steps for expressive properties
- Dynamics  $f$  are expensive to solve for long simulations
- Single Thread DFT:  $10s$  integration step requires 110 days
- Yet, essentially we are dealing with a time series prediction problem ...

**Can we learn the phase space dynamics with a ML algorithm?**

# Learning Dynamical Systems

- Learn dynamics  $f_\theta$  with NN from true dynamics  $f$

# Learning Dynamical Systems

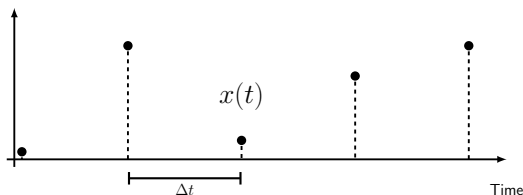
- Learn dynamics  $f_\theta$  with NN from true dynamics  $f$
- Integrate dynamics  $\hat{\dot{x}}(t) = f_\theta$  to obtain learned solution  $\hat{x}(t)$

# Learning Dynamical Systems

- Learn dynamics  $f_\theta$  with NN from true dynamics  $f$
- Integrate dynamics  $\hat{x}(t) = f_\theta$  to obtain learned solution  $\hat{x}(t)$
- Optimize  $f_\theta$  to predict the true solutions  $x(t)$

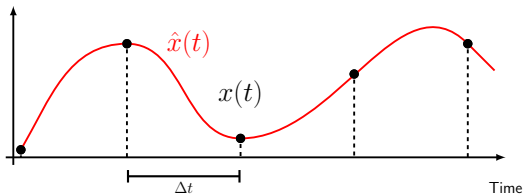
# Learning Dynamical Systems

- Learn dynamics  $f_\theta$  with NN from true dynamics  $f$
- Integrate dynamics  $\hat{\dot{x}}(t) = f_\theta$  to obtain learned solution  $\hat{x}(t)$
- Optimize  $f_\theta$  to predict the true solutions  $x(t)$



# Learning Dynamical Systems

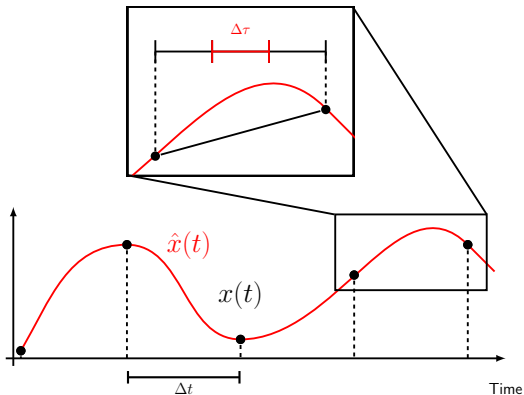
- Learn dynamics  $f_\theta$  with NN from true dynamics  $f$
- Integrate dynamics  $\hat{\dot{x}}(t) = f_\theta$  to obtain learned solution  $\hat{x}(t)$
- Optimize  $f_\theta$  to predict the true solutions  $x(t)$





# Learning Dynamical Systems

- Learn dynamics  $f_\theta$  with NN from true dynamics  $f$
- Integrate dynamics  $\hat{x}(t) = f_\theta$  to obtain learned solution  $\hat{x}(t)$
- Optimize  $f_\theta$  to predict the true solutions  $x(t)$



# Learning Dynamical Systems

## Model Architectures

- ODENetwork

$$\dot{x}(t) = \begin{bmatrix} \dot{r}(t) \\ \dot{p}(t) \end{bmatrix} = f \left( \begin{bmatrix} r(t) \\ p(t) \end{bmatrix}, t \right)$$

# Learning Dynamical Systems

## Model Architectures

- ODENetwork

$$\dot{x}(t) = \begin{bmatrix} \dot{r}(t) \\ \dot{p}(t) \end{bmatrix} = f \left( \begin{bmatrix} r(t) \\ p(t) \end{bmatrix}, t \right)$$

- HamiltonianNetwork

$$\dot{x}(t) = \begin{bmatrix} \dot{r}(t) \\ \dot{p}(t) \end{bmatrix} = \begin{bmatrix} \frac{\partial \mathcal{H}(r(t), p(t), t)}{\partial p(t)} \\ -\frac{\partial \mathcal{H}(r(t), p(t), t)}{\partial r(t)} \end{bmatrix}$$

# Learning Dynamical Systems

## Model Architectures

- ODENetwork

$$\dot{x}(t) = \begin{bmatrix} \dot{r}(t) \\ \dot{p}(t) \end{bmatrix} = f \left( \begin{bmatrix} r(t) \\ p(t) \end{bmatrix}, t \right)$$

- HamiltonianNetwork

$$\dot{x}(t) = \begin{bmatrix} \dot{r}(t) \\ \dot{p}(t) \end{bmatrix} = \begin{bmatrix} \frac{\partial \mathcal{H}(r(t), p(t), t)}{\partial p(t)} \\ -\frac{\partial \mathcal{H}(r(t), p(t), t)}{\partial r(t)} \end{bmatrix}$$

- RNN and LSTM

$$\dot{x}(t) = \begin{bmatrix} \dot{r}(t) \\ \dot{p}(t) \end{bmatrix} = f_{\theta} \left( \begin{bmatrix} r(t_0) \\ p(t_0) \end{bmatrix}, \dots, \begin{bmatrix} r(t) \\ p(t) \end{bmatrix} \right), t$$

# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization

# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information

# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information

# Learning Dynamical Systems with LSTM

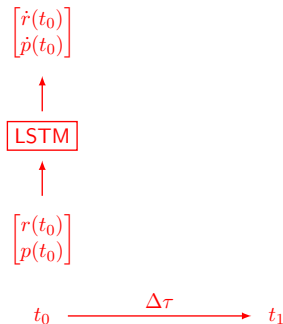
- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information





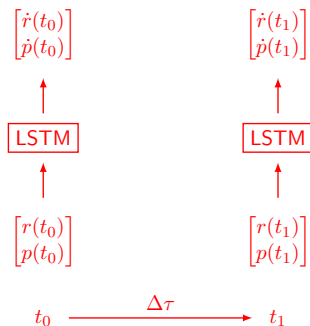
# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information



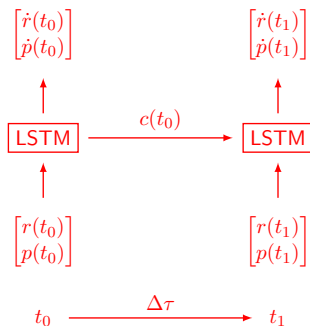
# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information



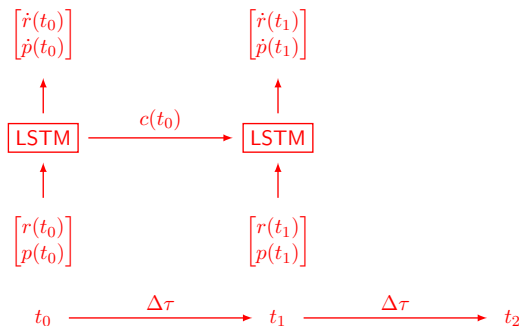
# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information



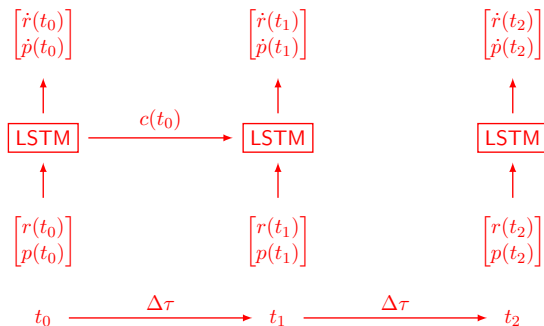
# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information



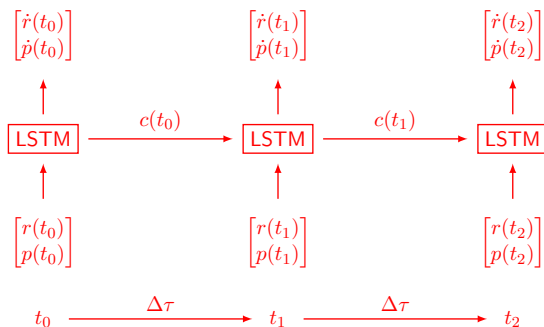
# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information



# Learning Dynamical Systems with LSTM

- Best performing due to fewest assumptions and flexible parameterization
- Memory cell  $c(t)$  to selectively read and write information

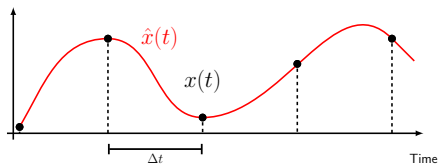


# Bi-Directional Interpolation of Differential Equation

- Use coarse, analytical MD to provide initial and final conditions

# Bi-Directional Interpolation of Differential Equation

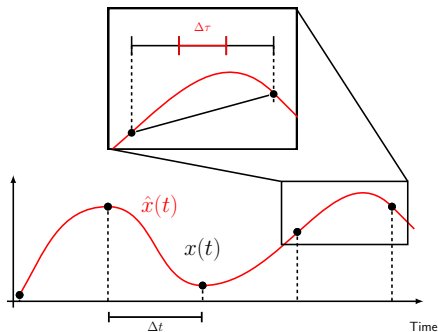
- Use coarse, analytical MD to provide initial and final conditions





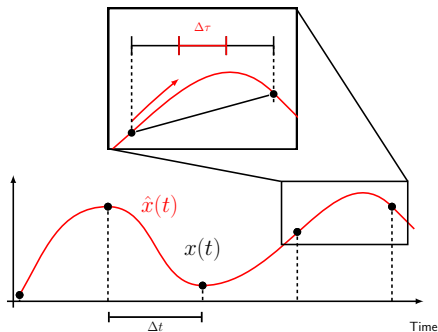
# Bi-Directional Interpolation of Differential Equation

- Use coarse, analytical MD to provide initial and final conditions



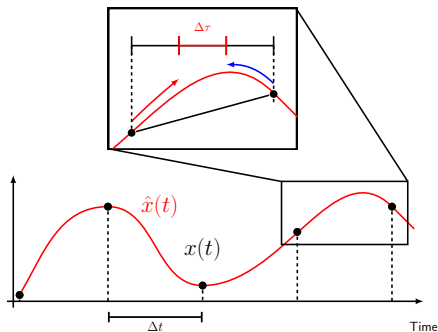
# Bi-Directional Interpolation of Differential Equation

- Use coarse, analytical MD to provide initial and final conditions
- Integrate dynamics **forward**



# Bi-Directional Interpolation of Differential Equation

- Use coarse, analytical MD to provide initial and final conditions
- Integrate dynamics **forward** and **backward** through time



# Bi-Directional Interpolation of Differential Equation

- Predict **forward solution**  $\overrightarrow{\hat{x}(t)}$  and **backward solution**  $\overleftarrow{\hat{x}(t)}$  with the **same** dynamics  $f_\theta$

# Bi-Directional Interpolation of Differential Equation

- Predict **forward solution**  $\overrightarrow{\hat{x}(t)}$  and **backward solution**  $\overleftarrow{\hat{x}(t)}$  with the **same** dynamics  $f_\theta$
- Use adiabatic connection to interpolate  $\overrightarrow{\hat{x}(t)}$  and  $\overleftarrow{\hat{x}(t)}$  to  $\hat{x}(t)$

# Bi-Directional Interpolation of Differential Equation

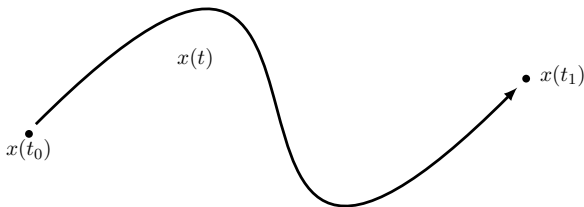
- Predict **forward solution**  $\overrightarrow{\hat{x}(t)}$  and **backward solution**  $\overleftarrow{\hat{x}(t)}$  with the **same** dynamics  $f_\theta$
- Use adiabatic connection to interpolate  $\overrightarrow{\hat{x}(t)}$  and  $\overleftarrow{\hat{x}(t)}$  to  $\hat{x}(t)$

$$\hat{x}(t) = (1 - \lambda(t)) \overrightarrow{\hat{x}(t)} + \lambda(t) \overleftarrow{\hat{x}(t)} \quad (1)$$

# Bi-Directional Interpolation of Differential Equation

- Predict **forward solution**  $\overrightarrow{\hat{x}(t)}$  and **backward solution**  $\overleftarrow{\hat{x}(t)}$  with the **same** dynamics  $f_\theta$
- Use adiabatic connection to interpolate  $\overrightarrow{\hat{x}(t)}$  and  $\overleftarrow{\hat{x}(t)}$  to  $\hat{x}(t)$

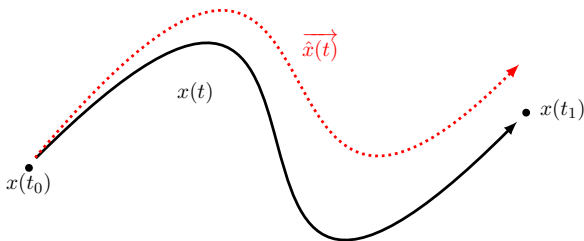
$$\hat{x}(t) = (1 - \lambda(t)) \overrightarrow{\hat{x}(t)} + \lambda(t) \overleftarrow{\hat{x}(t)} \quad (1)$$



# Bi-Directional Interpolation of Differential Equation

- Predict **forward solution**  $\overrightarrow{\hat{x}(t)}$  and **backward solution**  $\overleftarrow{\hat{x}(t)}$  with the **same** dynamics  $f_\theta$
- Use adiabatic connection to interpolate  $\overrightarrow{\hat{x}(t)}$  and  $\overleftarrow{\hat{x}(t)}$  to  $\hat{x}(t)$

$$\hat{x}(t) = (1 - \lambda(t)) \overrightarrow{\hat{x}(t)} + \lambda(t) \overleftarrow{\hat{x}(t)} \quad (1)$$

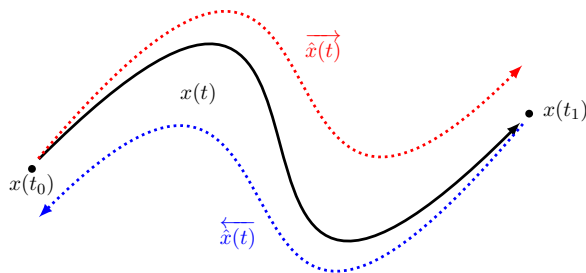




# Bi-Directional Interpolation of Differential Equation

- Predict **forward solution**  $\overrightarrow{\hat{x}(t)}$  and **backward solution**  $\overleftarrow{\hat{x}(t)}$  with the **same** dynamics  $f_\theta$
- Use adiabatic connection to interpolate  $\overrightarrow{\hat{x}(t)}$  and  $\overleftarrow{\hat{x}(t)}$  to  $\hat{x}(t)$

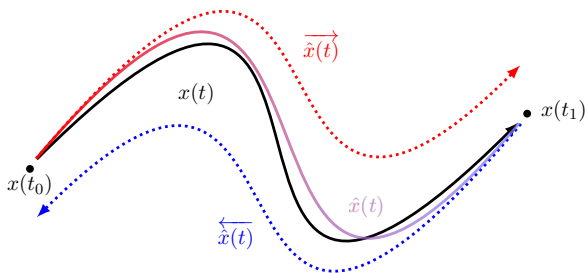
$$\hat{x}(t) = (1 - \lambda(t)) \overrightarrow{\hat{x}(t)} + \lambda(t) \overleftarrow{\hat{x}(t)} \quad (1)$$



# Bi-Directional Interpolation of Differential Equation

- Predict **forward solution**  $\overrightarrow{\hat{x}(t)}$  and **backward solution**  $\overleftarrow{\hat{x}(t)}$  with the **same** dynamics  $f_\theta$
- Use adiabatic connection to interpolate  $\overrightarrow{\hat{x}(t)}$  and  $\overleftarrow{\hat{x}(t)}$  to  $\hat{x}(t)$

$$\hat{x}(t) = (1 - \lambda(t)) \overrightarrow{\hat{x}(t)} + \lambda(t) \overleftarrow{\hat{x}(t)} \quad (1)$$

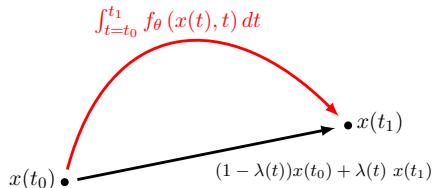


# Bi-Directional Interpolation of Differential Equation

- For time-reversible solutions, we obtain

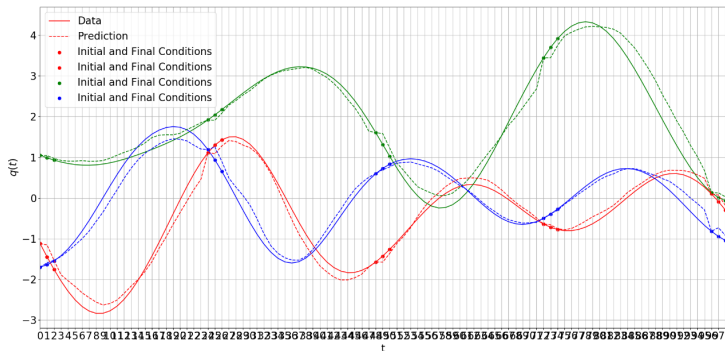
$$\begin{aligned}\hat{x}(t) &= (1 - \lambda(t)) \overrightarrow{\hat{x}(t)} + \lambda(t) \overleftarrow{\hat{x}(t)} \\ &= \underbrace{(1 - \lambda(t))x(t_0) + \lambda(t)x(t_1)}_{\text{low frequency components}} + \underbrace{\int_{t=t_0}^{t_1} f_{\theta}(x(t), t) dt}_{\text{high frequency components}}\end{aligned}$$

- Adiabatic connection frees the ML model to model high frequency signals



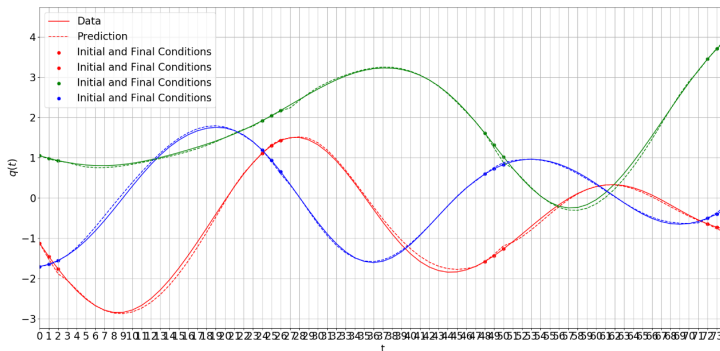
# Uni-Directional Interpolation of Differential Equation

- Unidirectional LSTM architecture for Benzene MD trajectory interpolating over 20 time steps



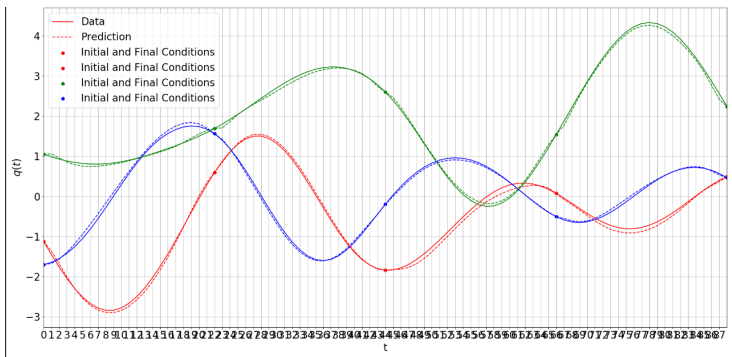
# Bi-Directional Interpolation of Differential Equation

- Bidirectional LSTM architecture for Benzene MD trajectory interpolating over 20 time steps
- Final condition and additional bidirectional training smooth trajectories significantly



# Bi-Directional Interpolation of Differential Equation

- Single initial and final condition already good for sufficient performance by bidirectional LSTM



# Analysis of Interpolations

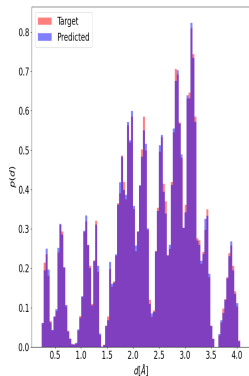


Figure:  
Keto-Malondialdehyde  
(100K)

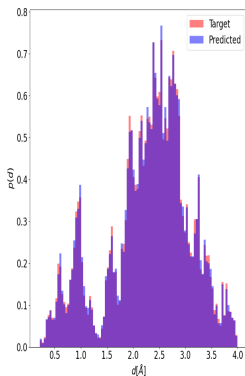


Figure:  
Keto-Malondialdehyde  
(300K)

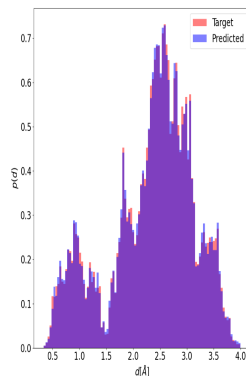
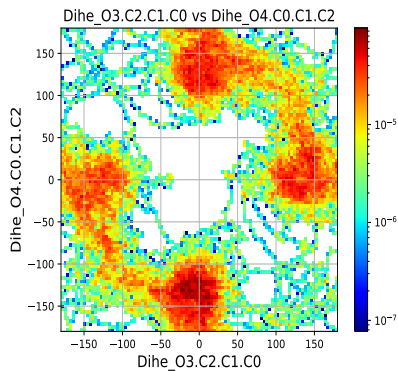
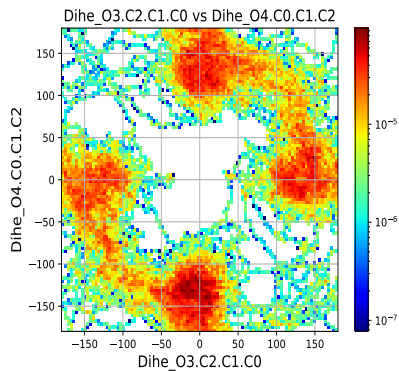


Figure:  
Keto-Malondialdehyde  
(500K)

# Analysis of Interpolations



**Figure:** Ground Truth Free Energy  
Keto-Malondialdehyde (300K)



**Figure:** Predicted Free Energy  
Keto-Malondialdehyde (300K)



# Future Work

- Adaptively switch between simulation and ML prediction

# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories

# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation

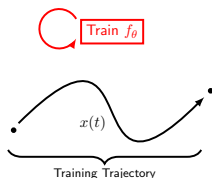
# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation



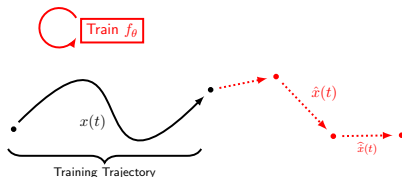
# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation



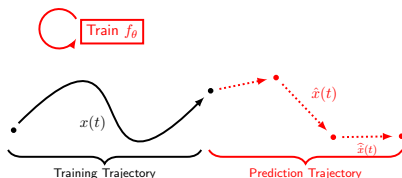
# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation



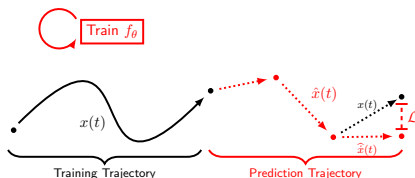
# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation



# Future Work

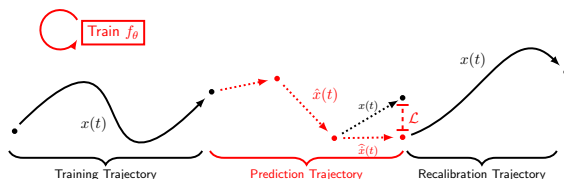
- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation





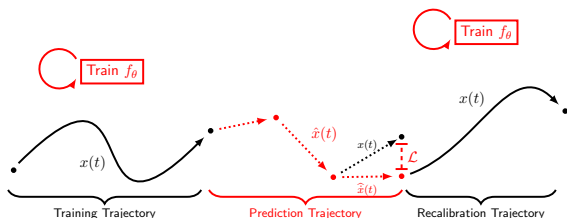
# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation



# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation



# Future Work

- Adaptively switch between simulation and ML prediction
- Leverage speed of ML prediction for smooth sub-trajectories
- Regularly monitor ML prediction performance with parallel simulation

