

ԱՐԻՇ Ե՝ ՄԻՋԵԴԻՐԸ 2020 ԿՅՈՒ



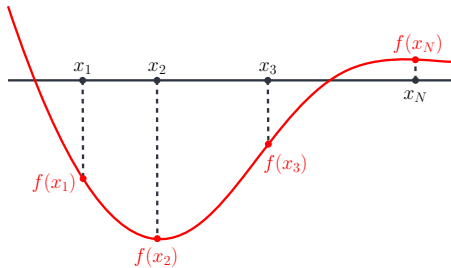
Numerical Integration

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Setting

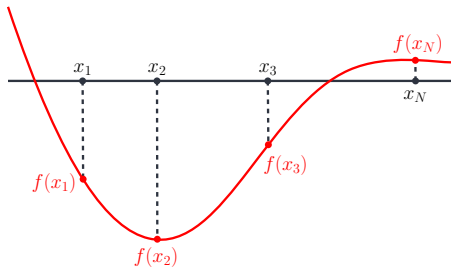


- Approximate

$$\int_a^b f(x)dx \approx \sum_{n=1}^N w_n f(x_n), \quad x \in \mathbb{R}$$

- Nodes x_n and corresponding function values $f(x_n)$

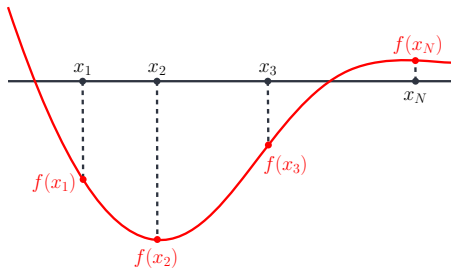
Numerical integration (quadrature)



Key idea

Approximate f using an interpolating function that is easy to integrate (e.g., polynomial)

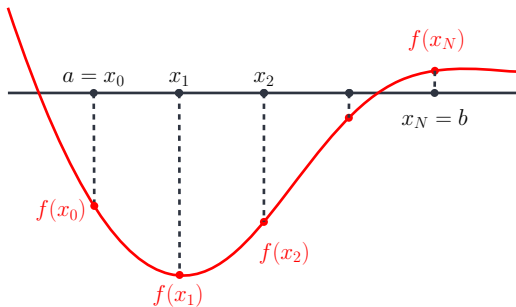
Quadrature approaches



Quadrature	Interpolant	Nodes
Newton–Cotes	low-degree polynomials	equidistant
Gaussian	orthogonal polynomials	roots of polynomial
Bayesian	Gaussian process	user defined

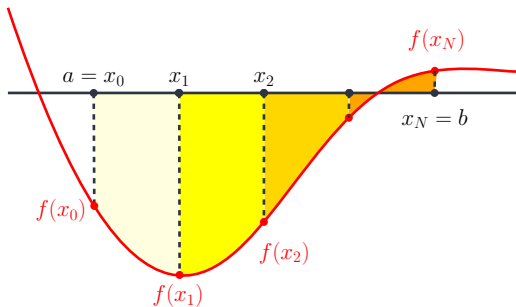
Newton–Cotes Quadrature

Overview



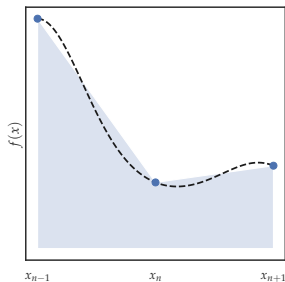
- **Equidistant nodes** $a = x_0, \dots, x_N = b$ \ggg Partition interval $[a, b]$
- Approximate f in each partition with a **low-degree polynomial**

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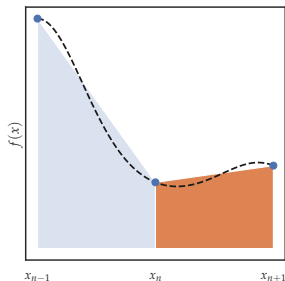
- **Equidistant nodes** $a = x_0, \dots, x_N = b$ \ggg Partition interval $[a, b]$
- Approximate f in each partition with a **low-degree polynomial**
- Compute integral for each partition analytically and sum them up

Trapezoidal rule



- ▶ Partition $[a, b]$ into N segments with equidistant nodes x_n
- ▶ **Locally linear approximation** of f between nodes

Trapezoidal rule (2)

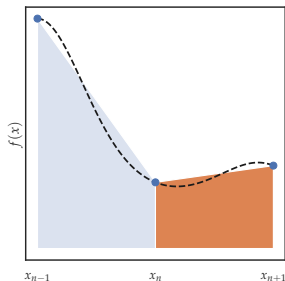


- Area of a trapezoid with corners $(x_n, x_{n+1}, f(x_{n+1}), f(x_n))$

$$\int_{x_n}^{x_{n+1}} f(x) dx \approx \frac{h}{2} (f(x_n) + f(x_{n+1}))$$

$h := |x_{n+1} - x_n|$ \gg Distance between nodes

Trapezoidal rule (2)



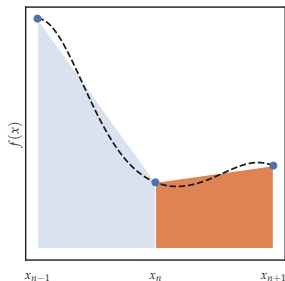
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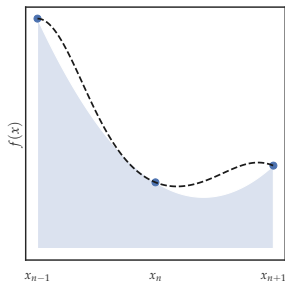
$$h := |x_{n+1} - x_n| \quad \gg \text{Distance between nodes}$$

- Error $\mathcal{O}(h^2)$

- Full integral:

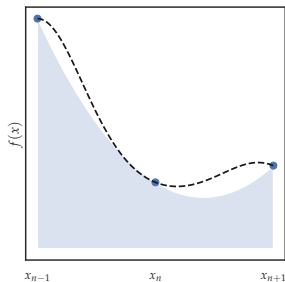
$$\int_a^b f(x) dx \approx \frac{h}{2} (f_0 + 2f_1 + \cdots + 2f_{N-1} + f_N), \quad f_n := f(x_n)$$

Simpson's rule



- Partition $[a, b]$ into N segments with equidistant nodes x_n
- **Locally quadratic approximation** of f connecting triplets $(f(x_{n-1}), f(x_n), f(x_{n+1}))$

Simpson's rule (2)

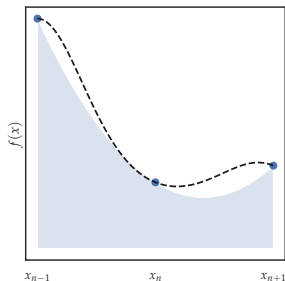


► Area of segment:

$$\int_{x_{n-1}}^{x_{n+1}} f(x) dx \approx \frac{h}{3} (f_{n-1} + 4f_n + f_{n+1})$$

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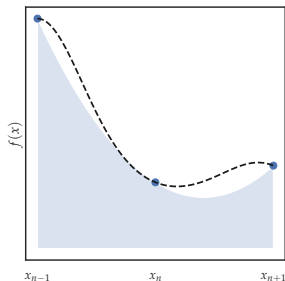
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► Error: $\mathcal{O}(h^4)$

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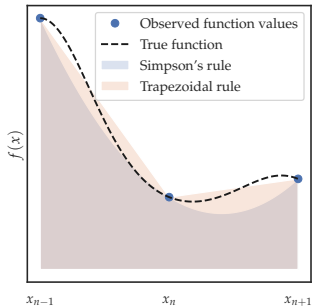
► Error: $\mathcal{O}(h^4)$

► Full integral:

$$\int_a^b f(x) dx \approx \frac{h}{3} (f_0 + 4f_1 + 2f_2 + 4f_3 + 2f_4 + \cdots + 2f_{N-2} + 4f_{N-1} + f_N)$$

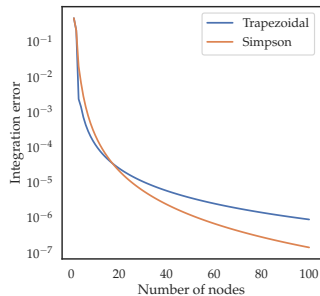
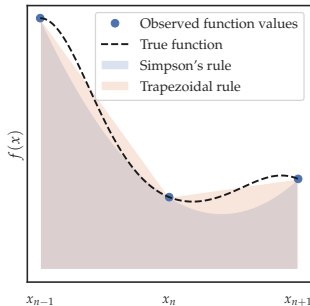
Example

$$\int_0^1 \exp(-x^2 - \sin(3x)^2) dx$$



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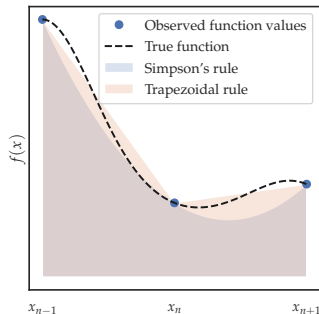
$$\int_0^1 \exp(-x^2 - \sin(3x)^2) dx$$



- ▶ Simpson's rule yields better approximations
- ▶ Very good approximations obtained fairly quickly

Summary: Newton–Cotes quadrature

- ▶ Approximate integrand between equidistant nodes with a low-degree polynomial (up to degree 6)
- ▶ Trapezoidal rule: linear interpolation
- ▶ Simpson's rule: quadratic interpolation
 - ▶▶ Better approximation and smaller integration error



Gaussian Quadrature

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- ▶ **Weight function** $w(x) \geq 0$ (and some other integration-related properties, which are satisfied if $w(x)$ is a pdf)
- ▶ Goal: Find nodes x_n and weights w_n , so that the approximation error is minimized

Central idea

- ▶ Quadrature nodes x_n are the roots of a family of **orthogonal polynomials**

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- ▶▶ Integral can be computed exactly by evaluating f N times at the optimal locations x_n (roots of an orthogonal polynomial) with corresponding optimal weights w_n
- ▶▶ **More accurate than Newton–Cotes** for the same number of evaluations (with some memory overhead)

Example: Gauß–Hermite quadrature

► Solve

$$\begin{aligned}\int f(x) \underbrace{\exp(-x^2)}_{w(x)} dx &= \int f(x) \frac{\sqrt{2\pi}}{\exp(-x^2/2)} \mathcal{N}(x|0, 1) dx \\ &= \sqrt{2\pi} \mathbb{E}_{x \sim \mathcal{N}(0,1)} \left[\frac{f(x)}{\exp(-x^2/2)} \right]\end{aligned}$$

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► With **change-of-variables trick** ►► Expectation w.r.t. a Gaussian measure

$$\mathbb{E}_{x \sim \mathcal{N}(\mu, \sigma^2)}[f(x)] \approx \frac{1}{\sqrt{\pi}} \sum_{n=1}^N w_n f(\sqrt{2}\sigma x_n + \mu).$$

Example: Gauß–Hermite quadrature (2)

- Follow general approximation scheme

$$\int f(x) \underbrace{\exp(-x^2)}_{w(x)} dx \approx \sum_{n=1}^N w_n f(x_n)$$

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- **Nodes** x_1, \dots, x_N are the roots of Hermite polynomial

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- **Weights** w_n are

$$w_n := \frac{2^{N-1} N! \sqrt{\pi}}{N^2 H_{N-1}^2(x_n)}$$

Overview (Stoer & Bulirsch, 2002)

$$\int_a^b w(x)f(x)dx \approx \sum_{n=1}^N w_n f(x_n)$$

$[a, b]$	$w(x)$	Orthogonal polynomial
$[-1, 1]$	1	Legendre polynomials
$[-1, 1]$	$(1 - x^2)^{-\frac{1}{2}}$	Chebyshev polynomials
$[0, \infty]$	exp $(-x)$	Laguerre polynomials
$[-\infty, \infty]$	exp $(-x^2)$	Hermite polynomials

Application areas

- ▶ Probabilities for rectangular bivariate/trivariate Gaussian and t distributions (Genz, 2004)
- ▶ Integrating out (marginalizing) a few hyper-parameters in a latent-variable model (INLA; Rue et al., 2009)
- ▶ Predictions with a Gaussian process classifier (GPFlow; Matthews et al., 2017)

Summary: Gaussian quadrature

- ▶ Orthogonal polynomials to approximate f
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- ▶ Higher accuracy than Newton–Cotes
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Summary: Gaussian quadrature

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- ▶ **Method of choice** for **low-dimensional problems** (1–3 dimensions)
- ▶ **Can't naturally deal with noisy observations**
- ▶ **Only works in low dimensions**
- ▶ Approaches that scale better with dimensionality
 - ▶▶ **Bayesian quadrature** (up to ≈ 10 dimensions)
 - ▶▶ **Monte Carlo estimation** (high dimensions)

Bayesian Quadrature

Bayesian quadrature: Setting and key idea

$$Z := \int f(\mathbf{x})p(\mathbf{x})d\mathbf{x} = \mathbb{E}_{\mathbf{x} \sim p}[f(\mathbf{x})]$$

- ▶ Function f is expensive to evaluate
- ▶ Integration in moderate (≤ 10) dimensions
- ▶ Deal with noisy function observations

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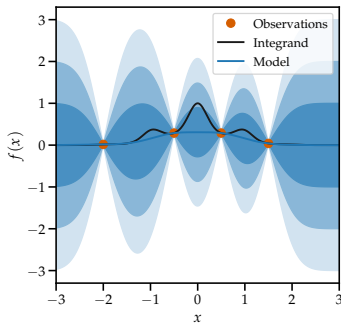
Key idea

- ▶ Phrase quadrature as a statistical inference problem
 - ▶▶ Probabilistic numerics (e.g., Hennig et al., 2015; Briol et al., 2015)
- ▶ Estimate distribution on Z using a dataset $\mathcal{D} := \{(\mathbf{x}_1, f(\mathbf{x}_1)), \dots, (\mathbf{x}_N, f(\mathbf{x}_N))\}$

Bayesian quadrature: How it works

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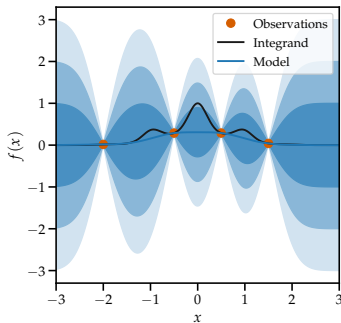
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- ▶ Estimate **distribution on Z** using a dataset $\mathcal{D} := \{(\mathbf{x}_1, f(\mathbf{x}_1)), \dots, (\mathbf{x}_N, f(\mathbf{x}_N))\}$
- ▶ Place (Gaussian process) **prior distribution on f** and determine the posterior via Bayes' theorem (Diaconis 1988; O'Hagan 1991; Rasmussen & Ghahramani 2003)
 - ▶▶ Distribution on f induces a distribution on Z

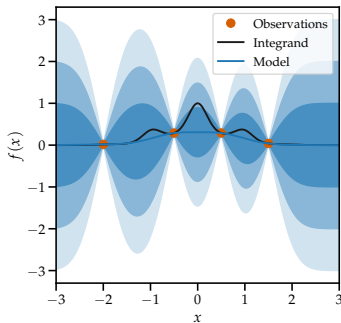


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 - Distribution on f induces a distribution on Z
- **Generalizes to noisy function observations**

$$y = f(\mathbf{x}) + \epsilon$$



Bayesian quadrature: Details

$$Z := \int f(\mathbf{x})p(\mathbf{x})d\mathbf{x}), \quad f \sim GP(0, k)$$

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$$\sigma_Z^2 = \iint k_{\text{post}}(\mathbf{x}, \mathbf{x}')p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' = \mathbb{E}_{\mathbf{x}, \mathbf{x}'}[k_{\text{post}}(\mathbf{x}, \mathbf{x}')]$$

Bayesian quadrature: Mean

$$\mathbb{E}_f[Z] = \mu_Z = \overbrace{\mathbb{E}_{\mathbf{x} \sim p}[\mu_{\text{post}}(\mathbf{x})]}^{\text{expected predictive mean}}$$

$$Z = \int f(\mathbf{x})p(\mathbf{x})d\mathbf{x}$$

$$f \sim GP(0, k)$$

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Training data: \mathbf{X}, \mathbf{y}

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$$\mathbb{E}_f[Z] = \int \overbrace{k(\mathbf{x}, \mathbf{X}) p(\mathbf{x}) d\mathbf{x} \boldsymbol{\alpha}}^{=:\mathbf{z}^\top} = \mathbf{z}^\top \boldsymbol{\alpha}$$

$$\mathbf{z}_n = \int k(\mathbf{x}, \mathbf{x}_n) p(\mathbf{x}) d\mathbf{x} = \mathbb{E}_{\mathbf{x} \sim p}[k(\mathbf{x}, \mathbf{x}_n)]$$

$$Z = \int f(\mathbf{x}) p(\mathbf{x}) d\mathbf{x}$$

$$f \sim GP(0, k)$$

$$p(Z) = \mathcal{N}(Z | \mu_Z, \sigma_Z^2)$$

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Bayesian quadrature: Variance

$$V_f[Z] = \sigma_Z^2 = \overbrace{\mathbb{E}_{\mathbf{x}, \mathbf{x}' \sim p}[k_{\text{post}}(\mathbf{x}, \mathbf{x}')]}$$

Bayesian quadrature: Variance

$$\begin{aligned} \mathbb{V}_f[Z] &= \sigma_Z^2 = \overbrace{\mathbb{E}_{\mathbf{x}, \mathbf{x}' \sim p}[k_{\text{post}}(\mathbf{x}, \mathbf{x}')] }^{\text{expected posterior covariance}} \\ &= \iint \underbrace{k(\mathbf{x}, \mathbf{x}')}_{\text{prior covariance}} - \underbrace{k(\mathbf{x}, \mathbf{X}) \mathbf{K}^{-1} k(\mathbf{X}, \mathbf{x}')}_{\text{information from training data}} p(\mathbf{x}) p(\mathbf{x}') d\mathbf{x} d\mathbf{x}' \end{aligned}$$

Bayesian quadrature: Variance

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Bayesian quadrature: Variance

$$\begin{aligned}\mathbb{V}_f[Z] &= \sigma_Z^2 = \overbrace{\mathbb{E}_{\mathbf{x}, \mathbf{x}' \sim p}[k_{\text{post}}(\mathbf{x}, \mathbf{x}')] }^{\text{expected posterior covariance}} \\&= \iint \underbrace{k(\mathbf{x}, \mathbf{x}')}_{\text{prior covariance}} - \underbrace{k(\mathbf{x}, \mathbf{X})\mathbf{K}^{-1}k(\mathbf{X}, \mathbf{x}')}_{\text{information from training data}} p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' \\&= \iint k(\mathbf{x}, \mathbf{x}')p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' - \underbrace{\int k(\mathbf{x}, \mathbf{X})p(\mathbf{x})d\mathbf{x}}_{=\mathbf{z}^\top} \\&= \mathbb{E}_{\mathbf{x}, \mathbf{x}'}[k(\mathbf{x}, \mathbf{x}')] - \mathbf{z}^\top\end{aligned}$$

Bayesian quadrature: Variance

$$\begin{aligned}\mathbb{V}_f[Z] &= \sigma_Z^2 = \overbrace{\mathbb{E}_{\mathbf{x}, \mathbf{x}' \sim p}[k_{\text{post}}(\mathbf{x}, \mathbf{x}')] }^{\text{expected posterior covariance}} \\&= \iint \underbrace{k(\mathbf{x}, \mathbf{x}')}_{\text{prior covariance}} - \underbrace{k(\mathbf{x}, \mathbf{X})\mathbf{K}^{-1}k(\mathbf{X}, \mathbf{x}')}_{\text{information from training data}} p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' \\&= \iint k(\mathbf{x}, \mathbf{x}')p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' - \underbrace{\int k(\mathbf{x}, \mathbf{X})p(\mathbf{x})d\mathbf{x}}_{=\mathbf{z}^\top} \mathbf{K}^{-1} \\&= \mathbb{E}_{\mathbf{x}, \mathbf{x}'}[k(\mathbf{x}, \mathbf{x}')] - \mathbf{z}^\top \mathbf{K}^{-1}\end{aligned}$$

Bayesian quadrature: Variance

$$\begin{aligned}\mathbb{V}_f[Z] &= \sigma_Z^2 = \overbrace{\mathbb{E}_{\mathbf{x}, \mathbf{x}' \sim p}[k_{\text{post}}(\mathbf{x}, \mathbf{x}')] }^{\text{expected posterior covariance}} \\&= \iint \underbrace{k(\mathbf{x}, \mathbf{x}')}_{\text{prior covariance}} - \underbrace{k(\mathbf{x}, \mathbf{X})\mathbf{K}^{-1}k(\mathbf{X}, \mathbf{x}')}_{\text{information from training data}} p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' \\&= \iint k(\mathbf{x}, \mathbf{x}')p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' - \underbrace{\int k(\mathbf{x}, \mathbf{X})p(\mathbf{x})d\mathbf{x}}_{=\mathbf{z}^\top} \mathbf{K}^{-1} \underbrace{\int k(\mathbf{X}, \mathbf{x}')p(\mathbf{x}')d\mathbf{x}'}_{=\mathbf{z}'} \\&= \mathbb{E}_{\mathbf{x}, \mathbf{x}'}[k(\mathbf{x}, \mathbf{x}')] - \mathbf{z}^\top \mathbf{K}^{-1} \mathbf{z}'\end{aligned}$$

Bayesian quadrature: Variance

$$\begin{aligned}\mathbb{V}_f[Z] &= \sigma_Z^2 = \overbrace{\mathbb{E}_{\mathbf{x}, \mathbf{x}' \sim p}[k_{\text{post}}(\mathbf{x}, \mathbf{x}')] }^{\text{expected posterior covariance}} \\&= \iint \underbrace{k(\mathbf{x}, \mathbf{x}')}_{\text{prior covariance}} - \underbrace{k(\mathbf{x}, \mathbf{X})\mathbf{K}^{-1}k(\mathbf{X}, \mathbf{x}')}_{\text{information from training data}} p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' \\&= \iint k(\mathbf{x}, \mathbf{x}')p(\mathbf{x})p(\mathbf{x}')d\mathbf{x}d\mathbf{x}' - \underbrace{\int k(\mathbf{x}, \mathbf{X})p(\mathbf{x})d\mathbf{x}}_{=\mathbf{z}^\top} \mathbf{K}^{-1} \underbrace{\int k(\mathbf{X}, \mathbf{x}')p(\mathbf{x}')d\mathbf{x}'}_{=\mathbf{z}'} \\&= \mathbb{E}_{\mathbf{x}, \mathbf{x}'}[k(\mathbf{x}, \mathbf{x}')] - \mathbf{z}^\top \mathbf{K}^{-1} \mathbf{z}' \\&= \mathbb{E}_{\mathbf{x}, \mathbf{x}'}[k(\mathbf{x}, \mathbf{x}')] - \mathbb{E}_{\mathbf{x}}[k(\mathbf{x}, \mathbf{X})]\mathbf{K}^{-1}\mathbb{E}_{\mathbf{x}'}[k(\mathbf{X}, \mathbf{x}')] \end{aligned}$$

Computing kernel expectations

$$\mathbb{E}_{\mathbf{x} \sim p}[k(\mathbf{x}, \mathbf{X})], \quad \mathbb{E}_{\mathbf{x}, \mathbf{x}' \sim p}[k(\mathbf{x}, \mathbf{x}')]]$$

- Solve a different (easier) integration problem

Computing kernel expectations

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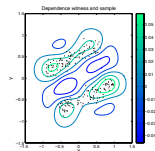
- Solve a different (easier) integration problem

Kernel k	Input distribution p	
	Gaussian	non-Gaussian
RBF/ polynomial/ trigonometric	analytical	analytical via importance-sampling trick
otherwise	Monte Carlo (numerical integration)	Monte Carlo (numerical integration)

Kernel expectations in other areas

$$\mathbb{E}_{\mathbf{x} \sim p}[k(\mathbf{x}, \mathbf{X})], \quad \mathbb{E}_{\mathbf{x}, \mathbf{x}' \sim p}[k(\mathbf{x}, \mathbf{x}')]]$$

- Kernel MMD
(e.g., Gretton et al., 2012)

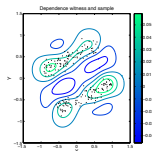


from Gretton et al. (2012)

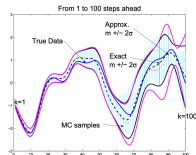
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- **Time-series analysis** with Gaussian processes
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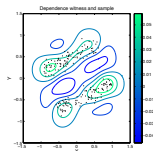


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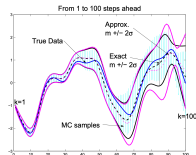
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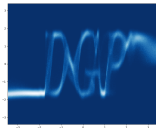
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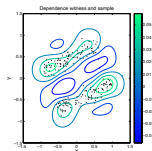


from Salimbeni et al. (2019)

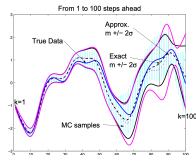
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(e.g., Damianou & Lawrence, 2013)
- **Model-based RL** with Gaussian processes
(e.g., Deisenroth & Rasmussen, 2011)



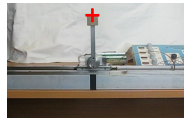
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Iterative procedure: Where to measure f next?

- Define an **acquisition function** (similar to Bayesian optimization)

Iterative procedure: Where to measure f next?

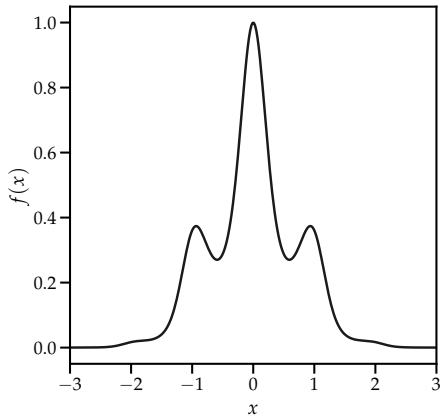
- Define an **acquisition function** (similar to Bayesian optimization)
- Example: Choose next node \mathbf{x}_{n+1} so that the **variance of the estimator is reduced maximally** (e.g., O'Hagan, 1991; Gunter et al., 2014)

$$\mathbf{x}_{n+1} = \operatorname{argmax}_{\mathbf{x}_*} \overbrace{\mathbb{V}[Z|\mathcal{D}]}^{\text{current variance}} - \mathbb{E}_{y_*} \left[\overbrace{\mathbb{V}[Z|\mathcal{D} \cup \{(\mathbf{x}_*, y_*)\}]}^{\text{new variance}} \right]$$

Example with EmuKit (Paley et al., 2019)

Compute

$$Z = \int_{-3}^3 e^{-x^2 - \sin^2(3x)} dx$$

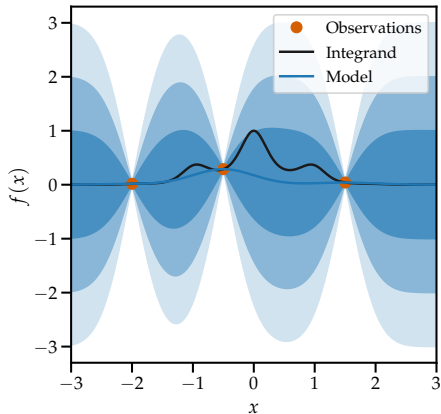


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- Fit Gaussian process to observations $f(x_1), \dots, f(x_n)$ at nodes x_1, \dots, x_n

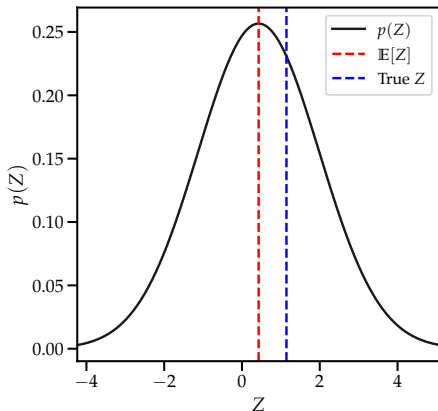


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- Determine $p(Z)$

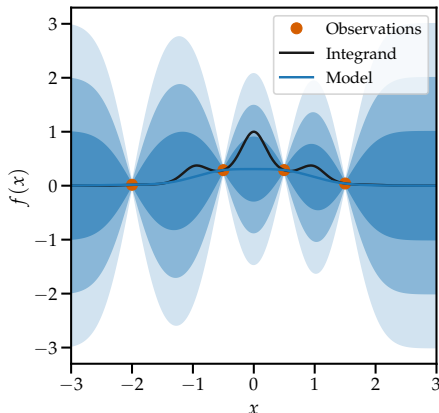


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- Determine $p(Z)$
- Find and include new measurement
 1. Find optimal node x_{n+1} by maximizing an acquisition function
 2. Evaluate integrand at x_{n+1}
 3. Update GP with $(x_{n+1}, f(x_{n+1}))$

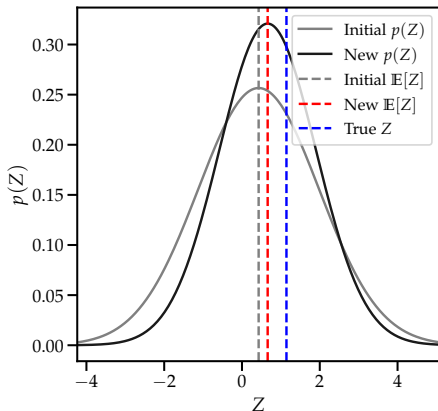


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- Compute updated $p(Z)$

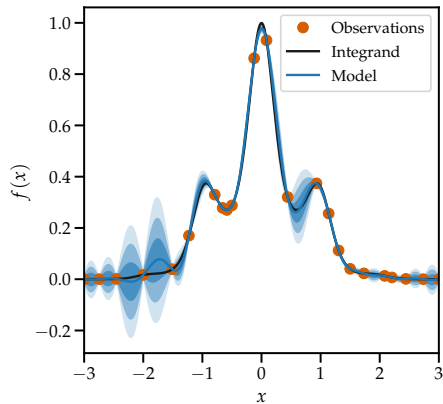


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- Find and include new measurement
- Compute updated $p(Z)$
- Repeat

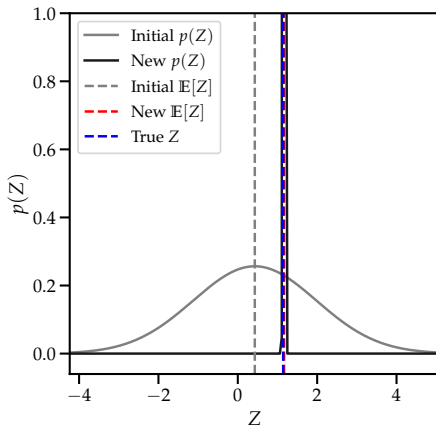


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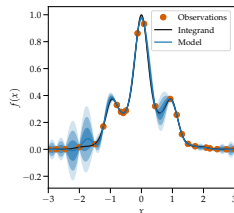
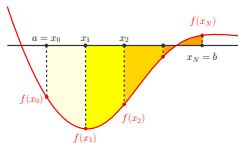


Summary

- Central approximation

$$\int f(\mathbf{x})d\mathbf{x} \approx \sum_{n=1}^N w_n f(\mathbf{x}_n)$$

- **Newton–Cotes:** Equidistant nodes \mathbf{x}_n , low-degree polynomial approximation of f
- **Gaussian quadrature:** Nodes \mathbf{x}_n as the roots of interpolating orthogonal polynomials of f
- **Bayesian quadrature:** Integration as a statistical inference problem; Global approximation of f using a Gaussian process; scales to moderate dimensions



►► Numerical integration is a really good idea in low dimensions

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