

lecture 23 Density Estimation & Normalizing Flows

last times : GAN & VAE learn density implicitly
(only access to samples, not $p(x)$)
Some tasks require $p(x)$

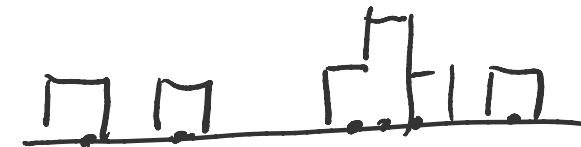
- likelihood of an observation (anomaly detection)
- computing expectation values, means, variances

Density Estimation

objective: learn the underlying pdf from which a set of iid samples was drawn

pdf : probability density function. $p(x) \geq 0$ $\int p(x) dx = 1$
 iid independent, identically distributed

1st try: histogram

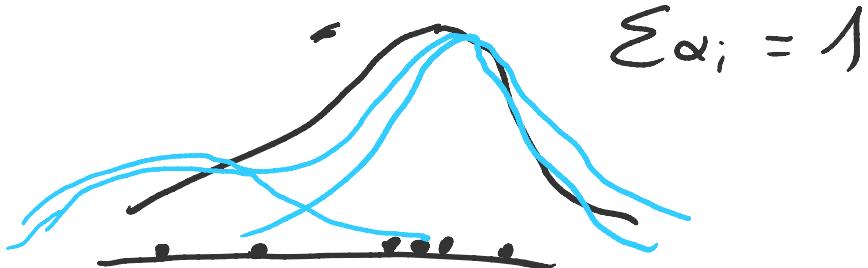


parametric

- fit parameters of known dist.

- GMM - Gaussian Mixture Models

$$p(x) = \sum_i \alpha_i N(\mu_i, \sigma_i)$$



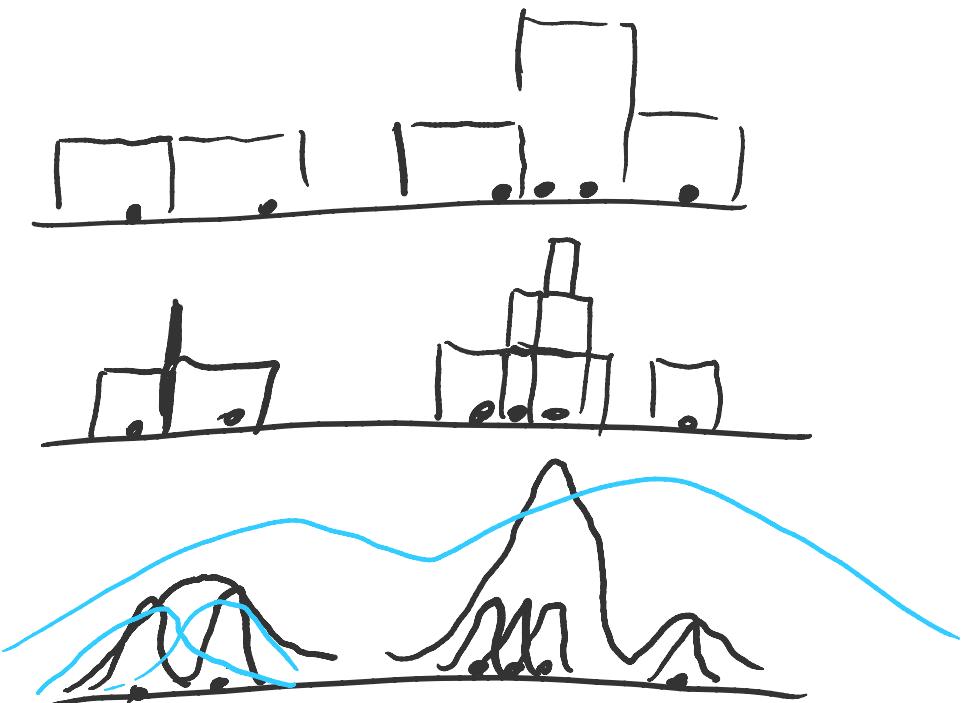
- + fast
- assumptions on data

& non-parametric DE

Kernel Density Estimation - KDE

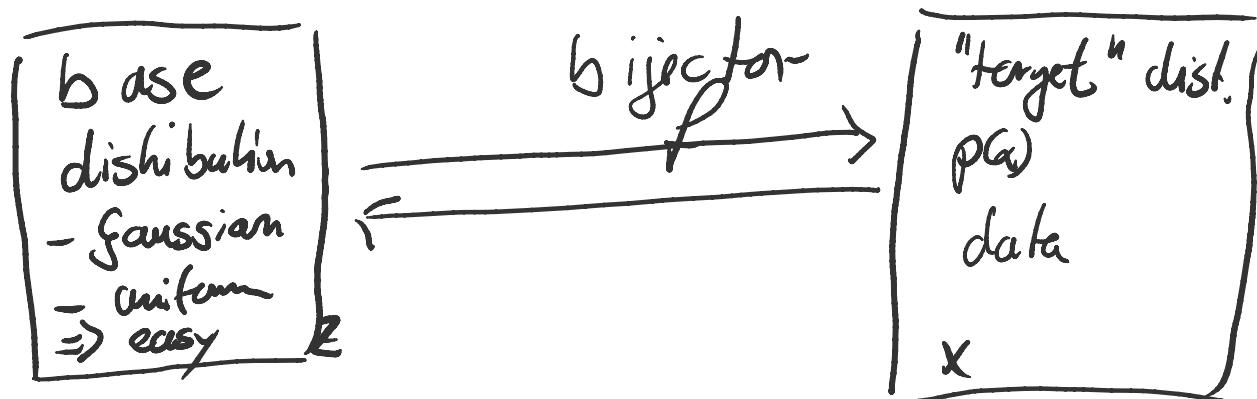
$$p(x) = \frac{1}{nh} \sum_{i=1}^n K\left(\frac{x-x_i}{h}\right)$$

↑
sum all data pts



- + no params (easy "learning") h... bad with
- + flexible
- numerically expensive (store full dataset)

NN as universal functions offer new possibilities \rightarrow one axis coordinate has permutations

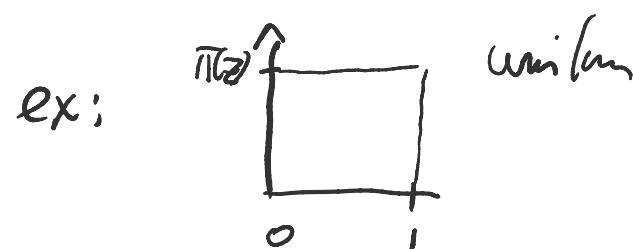


Coordinate function $\vec{x} = f(\vec{z})$

$$p(x) = \pi(z) \left| \det \frac{df}{dz} \right|^{-1}$$

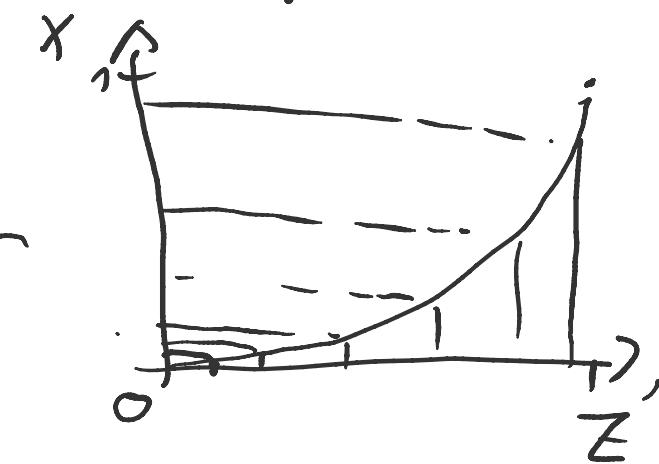
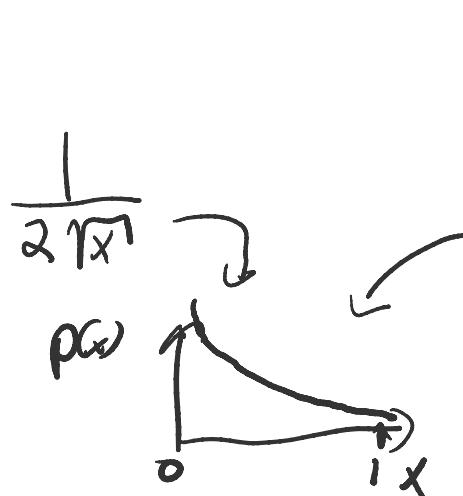
\rightarrow need Jacobian determinant

\rightarrow need inverse $\vec{z} = f^{-1}(\vec{x})$



$$x = f(z) = z^2$$

$$p(x) = 1 \cdot |2z|^{-1} = \frac{1}{2\sqrt{x}}$$



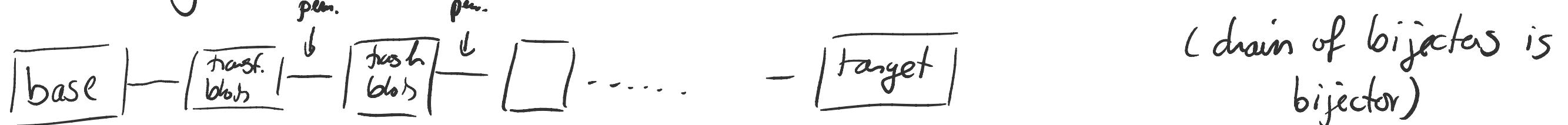
bijection: work both ways

$$\pi(z) \xrightarrow[\text{inference}]{\text{Sampling}} p(x)$$

what about using $f(z) = NN \downarrow$ - inverse?
 \hookrightarrow does not work : - Jacobian $\Theta(n^3)$

Normalizing Flows avoid these problems

by learning parameters of a series of invertible transformations w/ tractable Jacobian



$$x = c_k \circ c_{k-1} \circ \dots \circ c_1(\vec{z}_0) \quad \vec{z} \sim \pi_0(\vec{z}_0)$$

$$p(x) = \pi_0(\vec{z}_0) \cdot \prod_{k=1}^K \left| \det \frac{\partial c_k}{\partial z_{k-1}} \right|^{-1}$$

(S05.Q57 70)

Since we have $p(x)$, we can just train by $L_{\text{ss}} = -\log p(x)$

inside each block; assume the has partition factories

$$\vec{C}(\vec{z}, \vec{\mu}) = (C_1(z_1, \vec{\mu}_1), C_2(z_2, \vec{\mu}_2), \dots, C_n(z_n, \vec{\mu}_n))^T$$

$\vec{\mu}_i$ still depend on z_j ($i \neq j$) to capture all correlations

(+ external conditions)

there are 2 main architectures to tame Jacobians

① auto regressive models

assume $\vec{\mu}_i = \text{const}$; $\vec{\mu}_1(z_1), \dots, \vec{\mu}_i(z_1, z_2, z_3, \dots, z_{i-1}), \dots$

$$p(x_1), p(x_2 | x_1), p(x_i | x_1, x_2, \dots, x_{i-1})$$

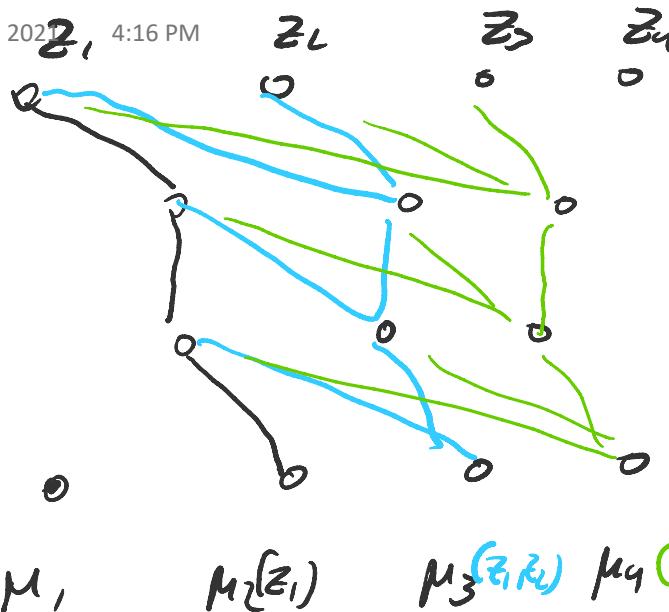
$$p(x) \approx \prod_{i=1}^n p(x_i | x_{1:i-1})$$

$$x_i = C_i(z_{1:i}) \quad J = (\Delta)$$

$$\det J = \prod_{i=1}^n J_{ii}$$

NN realization : MADE Masked Autoencoder for Density Estimation 1502.03509

Friday, April 16, 2021 4:16 PM



forward pass : single pass: all ps fast

inverse pass: loop n-times to get all z's slow

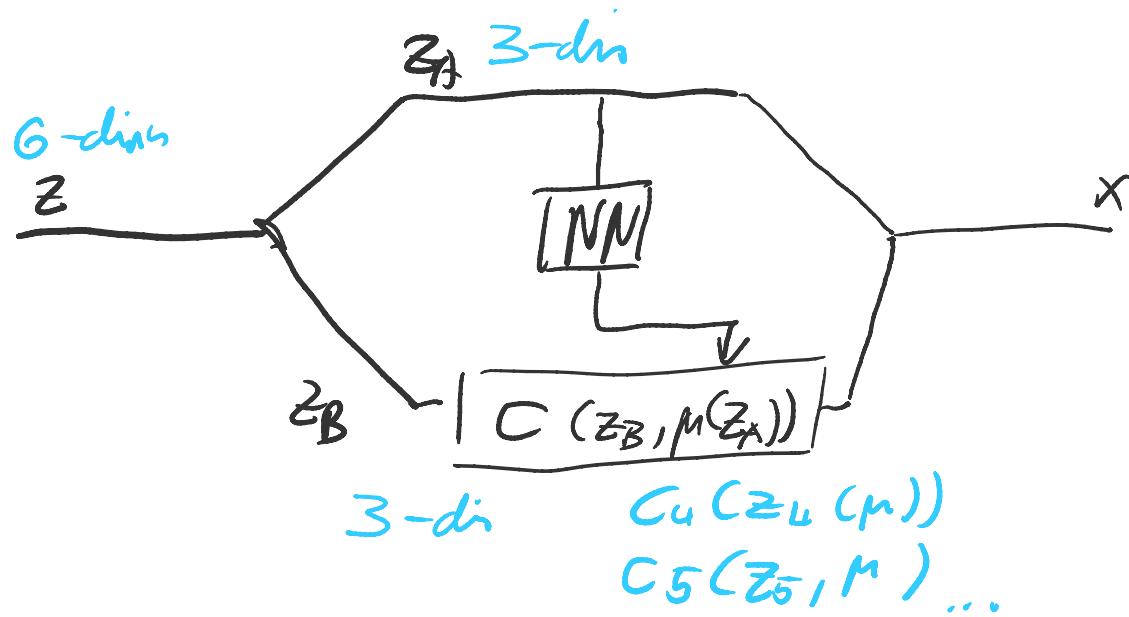
MAF	IAF
inference	Sampling

MAF: masked autoregressive flow 1705.07057

IAF: inverse autoregressive flow 1606.04934

⑦ Coupling Layer based flows (Real NVP 1605.08805)

split z in 2 sets z_A, z_B



forward

$$x_A = z_A$$

$$x_B = C_B(z_B, \mu(z_A))$$

inverse

$$z_A = x_A$$

$$z_B = C^{-1}(x_B; \mu(z_A))$$

$$|d\mathcal{A}| = \begin{vmatrix} 1 & 0 \\ \frac{\partial x_B}{\partial z_A} & \frac{\partial C_B}{\partial z_B} \end{vmatrix}$$

diagonal

equal speed
both directions

now about $C(z, \vec{\mu})$

↳ detailed choice depends on domain

base gaussian : $-\infty, +\infty$

uniform : $0, 1$

log, b
sigmoid

- affine coupling layer $C(z, \vec{\mu}) = z \odot \exp(s) + t = x$
 $z' \rightarrow NN \rightarrow s, t$

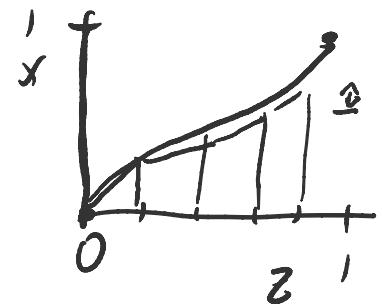
↳ inverse: $(x - t) \odot \exp(-s) = z$

(not as expensive)

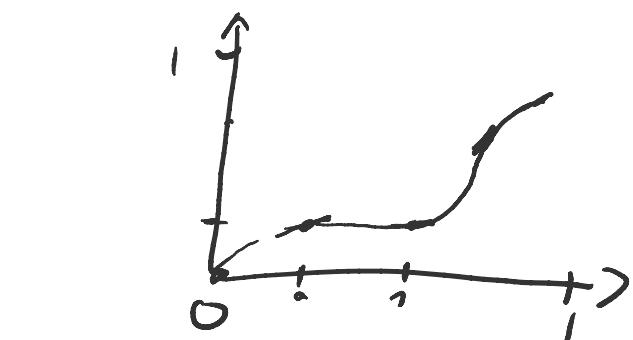
$$|\det J| = \exp(\varepsilon s)$$

- piecewise splines (for finite domain)

1808.03856



- PW - linear
quadratic, cubic



- Rational Quadratic spline

$$C = \frac{a_2 \alpha^2 + a_1 \alpha + a_0}{b_2 \alpha^2 + b_1 \alpha + b_0}$$

1906.04032

& ... where you are in the bin

a_i, b_i given by NN

$$\begin{aligned}x_1 &= C_1(z_1, \mu_1^{\text{cost}}) & \rightarrow p(x_1) \\x_2 &= C_2(z_2, \mu_2(z_1)) & p(x_2 | x_1) \\x_3 &= C_3(z_3, \mu_3(z_1, z_2)) & p(x_3 | x_1, x_2) \\&\quad \ddots\end{aligned}$$