Uncertainty quantification via codimension one domain partitioning and a new concentration inequality

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Outline

Introduction: Aim

Aim

We approach uncertainty quantification from the point of view of the certification problem: we want good (rigorous and sharp) upper bounds on

$$\mu[f(X) \leq \theta],$$

where

- $f : \mathcal{X} \to \mathbb{R}$ is a system / response function of interest;
- $X : \Omega \to \mathcal{X}$ represents the random inputs of f, with law μ;
- $\theta \in \mathbb{R}$ is some threshold for failure.

We do this so that we (hopefully) rigorously guarantee that

$$\mu[f(X) \leq \theta] \leq \epsilon,$$

where $\epsilon \in [0, 1]$ is a maximum acceptable probability of failure.

Introduction: Monte Carlo

Why not simply certify using Monte Carlo sampling?

Quantitative Reasons

For systems with small failure probability p, certification will take of the order of $p^{-2} \log p^{-1}$ samples (evaluations of f), which may be more expensive than the available resources permit.

Qualitative Reasons

Monte Carlo certification does not distinguish between the aleatoric uncertainty in the inputs X and the input parameter sensitivity of f. In the language of QMU (quantification of margins and uncertainties), it may be desirable to quantify margins (*e.g.* mean performance) and uncertainties (system sensitivity) separately.

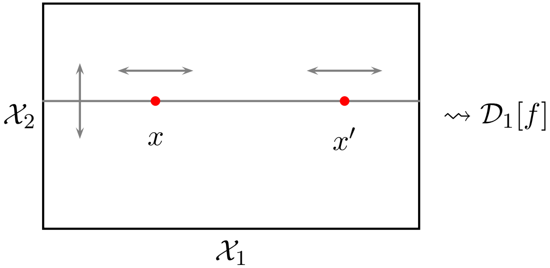
McDiarmid Diameters

Definition

For any function $f\colon \mathcal{X} = \mathcal{X}_1 \times \cdots \times \mathcal{X}_n \to \mathbb{R}$ and $i \in \{1, \dots, n\}$, the i^{th} McDiarmid subdiameter of f is defined by

$$\mathcal{D}_i[f] := \sup \left\{ |f(x) - f(x')| \,\middle|\, x_j = x'_j \in \mathcal{X}_j \text{ for } j \neq i \right\};$$

the McDiarmid diameter of f is $\mathcal{D}[f] := \left(\sum_{i=1}^{n} \mathcal{D}_i[f]^2 \right)^{1/2}$.



McDiarmid's Inequality

$$\mathcal{D}[f]^2 = \sum_{i=1}^{n} \left(\sup \left\{ |f(x) - f(x')| \,\middle|\, x_j = x'_j \in \mathcal{X}_j \text{ for } j \neq i \right\} \right)^2 .$$

Theorem (McDiarmid 1989)

For every product measure μ on $\mathcal{X} = \mathcal{X}_1 \times \cdots \times \mathcal{X}_n$ such that $\mathbb{E}[|f|]$ is finite (i.e. the components of $X = (X_1, \ldots, X_n)$ are independent random variables), and for every $r > 0$,

$$\mu[f - \mathbb{E}[f] \geq r] \leq \exp\left(-\frac{2r^2}{\mathcal{D}[f]^2} \right)$$

$$\mu[f - \mathbb{E}[f] \geq -r] \leq \exp\left(-\frac{2r^2}{\mathcal{D}[f]^2} \right) .$$

Certification using McDiarmid's Inequality

McDiarmid's inequality implies that

$$\mu[f \leq \theta] \leq \exp\left(-\frac{2(\mathbb{E}[f] - \theta)_+^2}{\mathcal{D}[f]^2}\right).$$

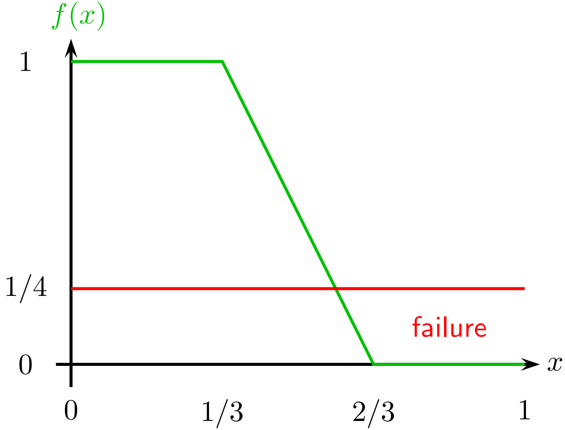
This provides a rigorous certification criterion in terms of the performance margin $(\mathbb{E}[f] - \theta)_+$ and the McDiarmid diameter $\mathcal{D}[f]$: the system is certified as safe if

$$\exp\left(-\frac{2(\mathbb{E}[f] - \theta)_+^2}{\mathcal{D}[f]^2}\right) \leq \epsilon.$$

Application of McDiarmid's inequality is not an ideal method:

- determination of $\mathcal{D}[f]$ requires n $(n+1)$-dimensional global optimizations — this may be expensive if f is irregular;
- $\mathcal{D}[f]$ is a global sensitivity measure — because of this, McDiarmid's inequality is often not sharp.

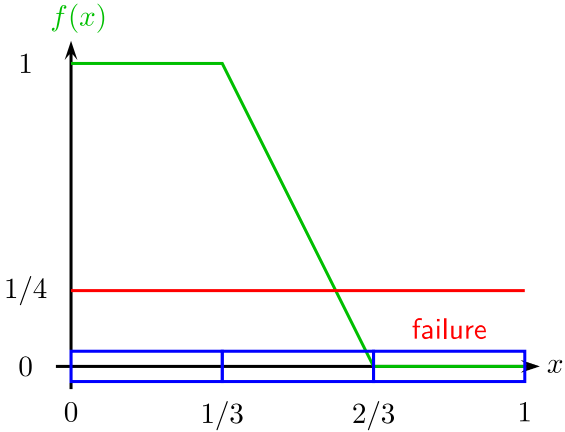
McDiarmid's Inequality is Not Sharp



Exact probability of failure if $\mu =$ uniform: $\mu[f \leq \frac{1}{4}] = \frac{5}{12} \approx 0.42$

McDiarmid's bound: $\mu[f \leq \frac{1}{4}] \leq e^{-1/8} \approx 0.88$

McDiarmid's Inequality is Not Sharp



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McDiarmid's bound on each third: $\mu[f \leq \frac{1}{4}] \leq \frac{1}{3}(0 + e^{-1/8} + 1) \approx 0.63$

McDiarmid's Inequality with Partitioning

Let $\mathcal{P}$ be a finite or countable partition of $\mathcal{X}$ into pairwise-disjoint measurable rectangles, and let μ be any product measure on $\mathcal{X}$ for which $\mathbb{E}_\mu[|f|]$ is finite. Then

$$\begin{aligned}
\mu[f \leq \theta] &= \sum_{A \in \mathcal{P}} \mu([f \leq \theta] \cap A) \\
&= \sum_{A \in \mathcal{P}} \mu(A) \mu[f \leq \theta | A] \\
&\leq \sum_{A \in \mathcal{P}} \mu(A) \exp\left(- \frac{2(\mathbb{E}[f|A] - \theta)_+^2}{\mathcal{D}[f|A]^2} \right) \\
&=: \overline{\mu_{\mathcal{P}}}[f \leq \theta].
\end{aligned}$$

Error Bound

Proposition (Error bound)

Let $f \colon \mathcal{X} \to \mathbb{R}$ be measurable and let $\mathcal{P}$ be a partition of $\mathcal{X}$. Then, for every $\varepsilon > 0$, and for all sufficiently small $\delta > 0$,

$$0 \leq \overline{\mu_{\mathcal{P}}}[f \leq \theta] - \mu[f \leq \theta] < \varepsilon + \sup_{A \in \mathcal{P}_\delta} \exp\left(- \frac{2 \left(\delta - \sum_{j=1}^{n} \mathcal{D}_j[f|A] \right)_+^2}{\mathcal{D}[f|A]^2} \right),$$

where

$$\mathcal{P}_\delta := \{ A \in \mathcal{P} \mid f(A) \cap (\theta + \delta, +\infty) \neq \varnothing \}.$$

I.e. the amount by which $\overline{\mu_{\mathcal{P}}}[f \leq \theta]$ is an over-estimate of the probability of failure is controlled by the McDiarmid subdiameters (*not* the metric diameter) of those $A \in \mathcal{P}$ on which f exceeds the threshold for success by more than δ *somewhere* in A.

Partitioning Algorithms

For simplicity, restrict attention to parameter spaces that are compact boxes in $\mathbb{R}^n$:

$$\mathcal{X} = [a_1, b_1] \times \cdots \times [a_n, b_n].$$

How can one *efficiently* construct a partition $\mathcal{P}$ of $\mathcal{X}$ for which $\overline{\mu_{\mathcal{P}}}[f \leq \theta]$ is nearly $\mu[f \leq \theta]$?

Naïve Method

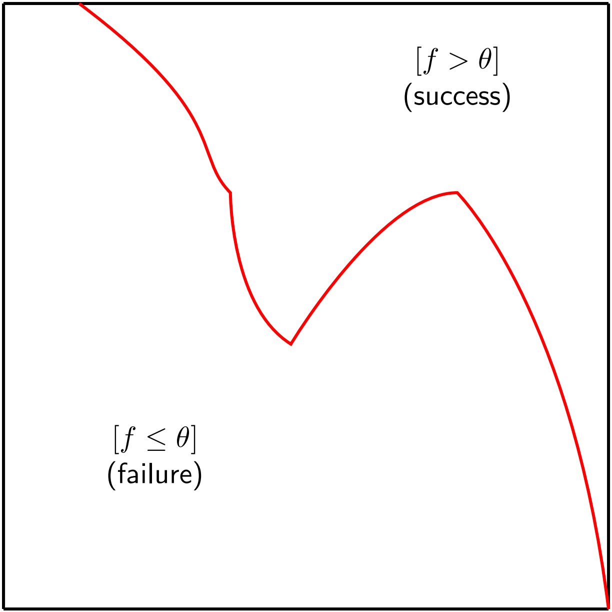
Construct a sequence $(\mathcal{P}(k))_{k \in \mathbb{N}}$ by bisecting each box $A \in \mathcal{P}(k)$ in each of the n coordinate directions to produce the boxes of $\mathcal{P}(k+1)$.

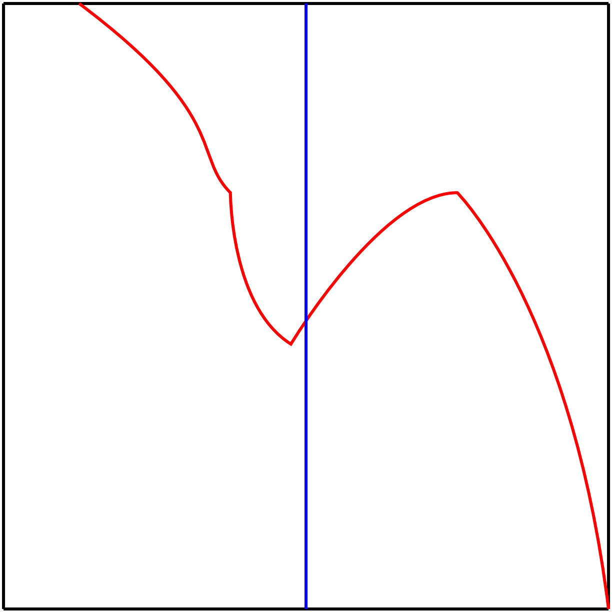
The naïve method is strongly affected by the curse of dimension: there are 2^n new boxes with each iteration. Therefore, we propose an algorithm in which the McDiarmid subdiameters are used as sensitivity indices to guide a codimension-one recursive partitioning scheme.

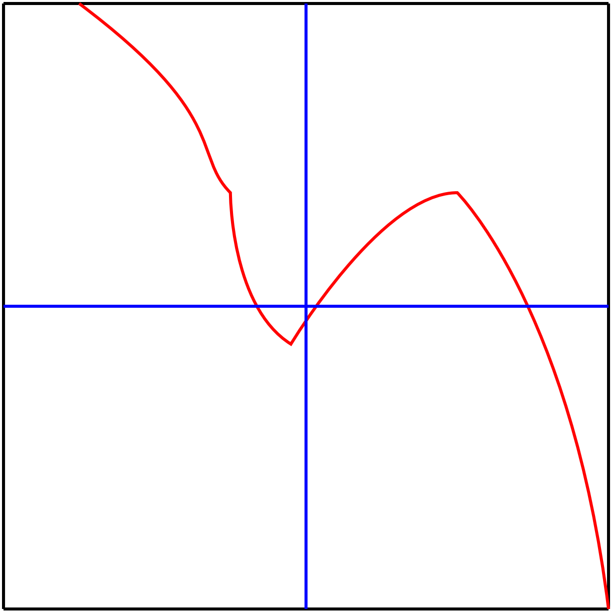
Codimension-One Recursive Partitioning Using Subdiameters (CORPUS)

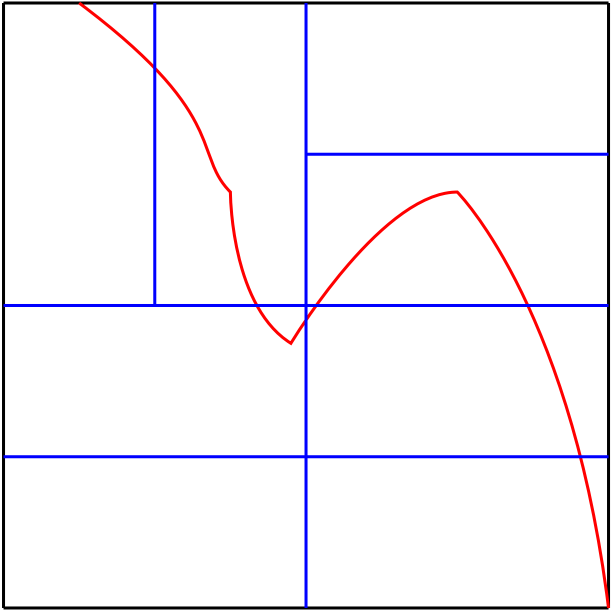
Recursively define a sequence of partitions $(\mathcal{P}(k))_{k\in\mathbb{N}}$ as follows: for each $A \in \mathcal{P}(k)$,

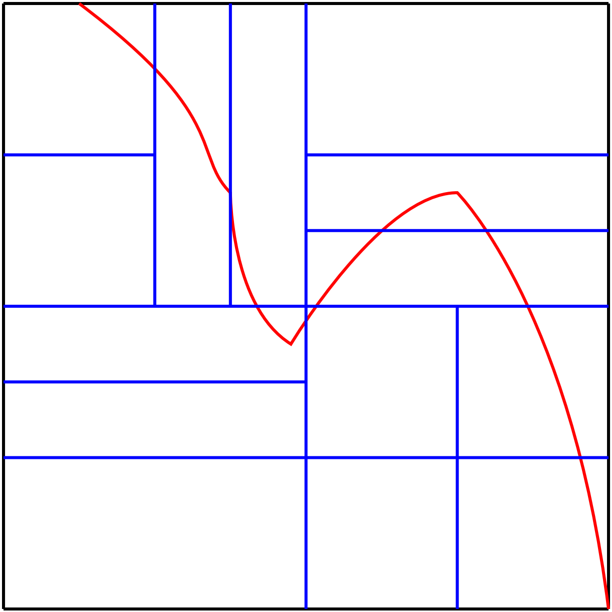
1. if $A \in \mathcal{P}(k)$ satisfies $\inf_{x\in A} f(x) > \theta$ (*i.e.* f always succeeds on A), then include A in $\mathcal{P}(k+1)$ as it is;
2. if $A \in \mathcal{P}(k)$ satisfies $\sup_{x\in A} f(x) \leq \theta$ (*i.e.* f always fails on A), then include A in $\mathcal{P}(k+1)$ as it is;
3. otherwise,
    1. determine $j \in \{1, \dots, n\}$ such that $\mathcal{D}_j[f|A]$ is maximal (choose one such j arbitrarily if there are multiple maximizers);
    2. set $c(A) := \int_A x \, \mathrm{d}x$, the geometric centre of A;
    3. bisect A by a hyperplane of codimension one (*i.e.* of dimension $n-1$) through $c(A)$ and normal to $\widehat{e}_j$, the unit vector in the j^{th} coordinate direction;
    4. include in $\mathcal{P}(k+1)$ the two subsets of A so generated, but not the original set A; the two new sets are called the *children* of A.

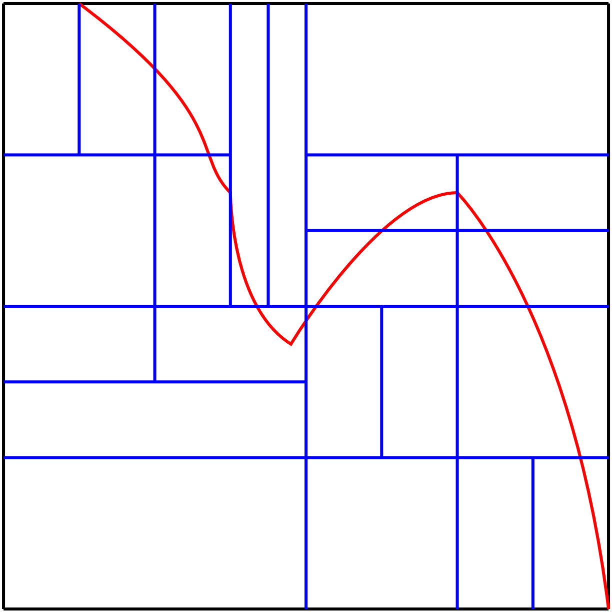

$[f > \theta]$
(success)
$[f \leq \theta]$
(failure)

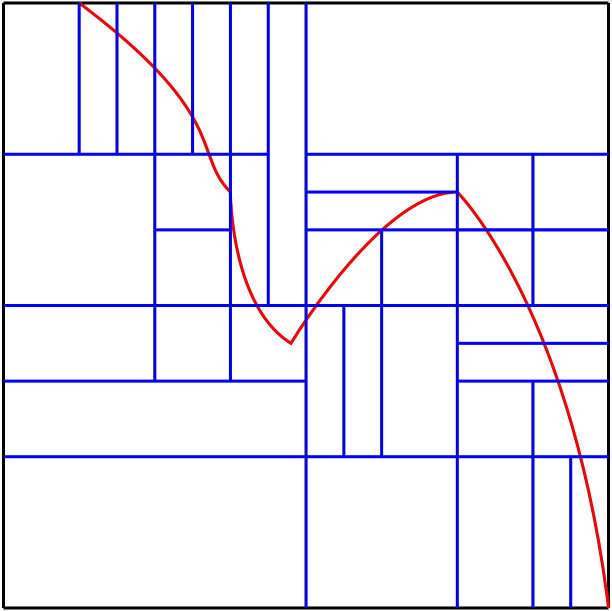












CORPUS Convergence Theorem

Theorem

For every bounded box $\mathcal{X} = \mathcal{X}_1 \times \cdots \times \mathcal{X}_n \subseteq \mathbb{R}^n$ and every uniformly continuous $f \colon \mathcal{X} \to \mathbb{R}$, the CORPUS algorithm generates a sequence of partitions $(\mathcal{P}(k))_{k \in \mathbb{N}}$ such that

$$\mu[f \leq \theta] = \lim_{k \to \infty} \overline{\mu_{\mathcal{P}(k)}}[f \leq \theta].$$

Sketch of Proof

It is enough to show that, for any initial box A, every generation-g child A' of A with g sufficiently large must satisfy one of the following:

$$\mathcal{D}_j[f|A'] \leq \frac{1}{2}\mathcal{D}_j[f|A] \text{ for all } j = 1, \dots, n, \text{ or}$$

$$\sup_{x \in A'} f(x) \leq \theta \text{ or } \inf_{x \in A'} f(x) > \theta.$$

Hypervelocity Impact

Figure: Caltech's Small Particle Hypervelocity Impact Range (SPHIR): a two-stage light gas gun that launches 1–$50\,\mathrm{mg}$ projectiles at speeds of 2–$10\,\mathrm{km}\cdot\mathrm{s}^{-1}$.

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Hypervelocity Impact: Surrogate Model

Experimentally-derived deterministic surrogate model for the perforation area (in mm^2):

- plate thickness $h \in [1.52, 2.67]\,\mathrm{mm}$;
- impact obliquity $\alpha \in [0, \frac{\pi}{6}]$;
- impact speed $v \in [2.1, 2.8]\,\mathrm{km} \cdot \mathrm{s}^{-1}$.

$$f(h, \alpha, v) := 10.396 \left(\left(\frac{h}{1.778} \right)^{0.476} (\cos \alpha)^{1.028} \tanh \left(\frac{v}{v_{\mathrm{bl}}} - 1 \right) \right)_+^{0.468}$$

The quantity $v_{\mathrm{bl}}(h, \alpha)$ given by

$$v_{\mathrm{bl}}(h, \alpha) := 0.579 \left(\frac{h}{(\cos \alpha)^{0.448}} \right)^{1.400}$$

is called the ballistic limit, the impact speed below which no perforation occurs. The failure event is non-perforation, *i.e.* $[f = 0] \equiv [f \leq 0]$.

Hypervelocity Impact: Surrogate Model

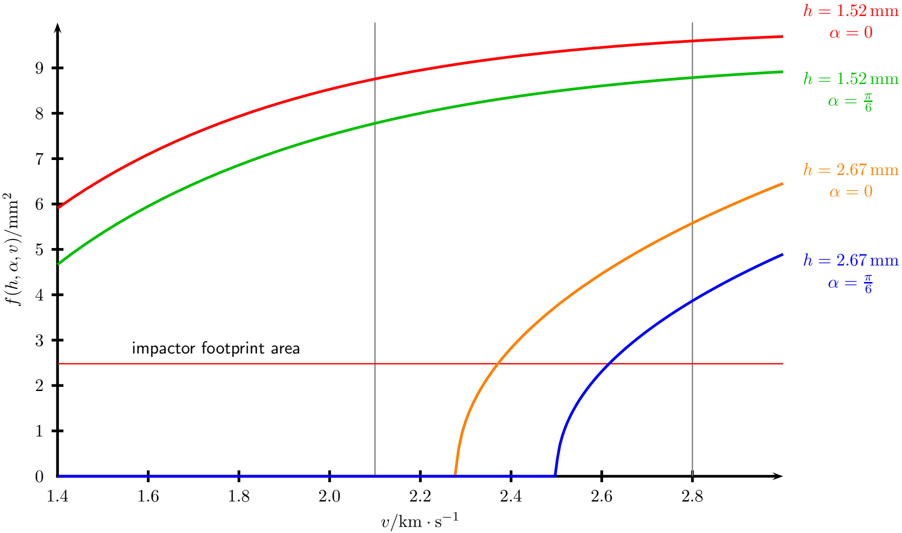


Figure: The surrogate perforation area model of the previous slide.

Hypervelocity Impact: Effect of Partitioning

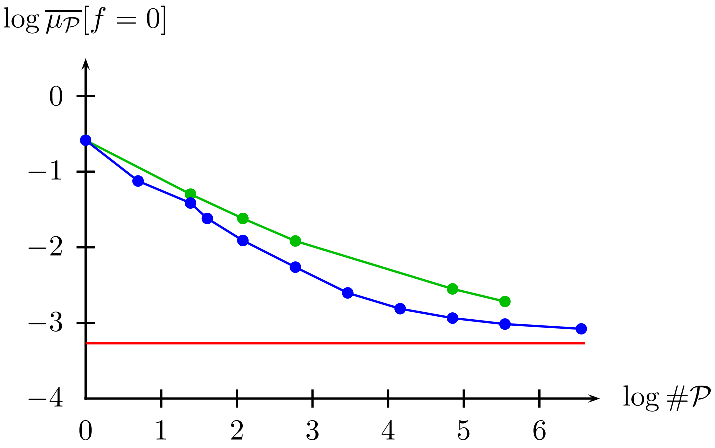


Figure: In blue, the $\overline{\mu_{\mathcal{P}}}$ upper bound on the failure probability versus the number of boxes $\#\mathcal{P}$ used by the CORPUS algorithm. In green, the corresponding upper bound obtained if all boxes are subdivided, instead of just those on which f both succeeds and fails. In red, the exact probability of failure.

Confidence in Empirical Bounds

Suppose that we are given a partition $\mathcal{P} = A_1 \uplus \dots \uplus A_K$ for which we know $\mu(A_k)$ and $\mathcal{D}[f|A_k]$ for each $k = 1, \dots, K$, but our knowledge of the local mean performance $\mathbb{E}[f|A_k]$ comes from m_k empirical samples:

$$\mathbb{E}[f|A_k] \rightsquigarrow \langle f|A_k \rangle := \frac{1}{m_k} \sum_{j=1}^{m_k} f(X^{(j)}).$$

It is not true that

$$\mu[f \leq \theta] \leq \sum_{k=1}^{K} \mu(A_k) \exp\left(- \frac{2(\langle f|A_k \rangle - \theta)_+^2}{\mathcal{D}[f|A_k]^2} \right);$$

however, it may be true, with acceptably high probability, that

$$\mu[f \leq \theta] \leq \sum_{k=1}^{K} \mu(A_k) \exp\left(- \frac{2(\langle f|A_k \rangle - \alpha_k - \theta)_+^2}{\mathcal{D}[f|A_k]^2} \right),$$

where $\alpha_k > 0$ are suitable margin hits.

McDiarmid's Inequality with an Empirical Mean

Theorem

Let $X^{(1)}, \dots, X^{(m)}$ *be* m *independent* μ*-distributed samples of* $\mathcal{X}$ *and let*

$$\langle f \rangle := \frac{1}{m} \sum_{j=1}^{m} f(X^{(j)})$$

be the associated empirical mean of f*. Then, for every* $\varepsilon > 0$*, with* μ*-probability at least* $1 - \varepsilon$ *on the* m *samples,*

$$\mu[f \leq \theta] \leq \exp\left(- \frac{2(\langle f \rangle - \alpha - \theta)_+^2}{\mathcal{D}[f]^2} \right),$$

$$\text{where } \alpha := \mathcal{D}[f] \sqrt{\frac{\log(1/\varepsilon)}{2m}}.$$

Partitioned McDiarmid's Inequality with Empirical Means

Given $\alpha = (\alpha_1, \dots, \alpha_K) \in \mathbb{R}^K$, let

$$H_\alpha(y) := \sum_{k=1}^{K} \mu(A_k) \exp\left(-\frac{2(\mathbb{E}[f|A_k] - y_k - \alpha_k - \theta)_+^2}{\mathcal{D}[f|A_k]^2} \right).$$

We seek a bound

$$\mu\Big[H_\alpha(Y) \leq \underbrace{H_\alpha(-\alpha)}_{\equiv \overline{\mu_{\mathcal{P}}}[f \leq \theta]}\Big] \leq \textbf{???}$$

where

$$Y_k := \mathbb{E}[f|A_k] - \langle f|A_k \rangle.$$

Note that each Y_k is a real-valued random variable that concentrates about its mean, 0: for any $r > 0$,

$$\mu[Y_k \geq r] \text{ and } \mu[Y_k \leq -r] \leq \exp\left(-\frac{2 m_k r^2}{\mathcal{D}[f|A_k]^2} \right).$$

Level Sets of H_α

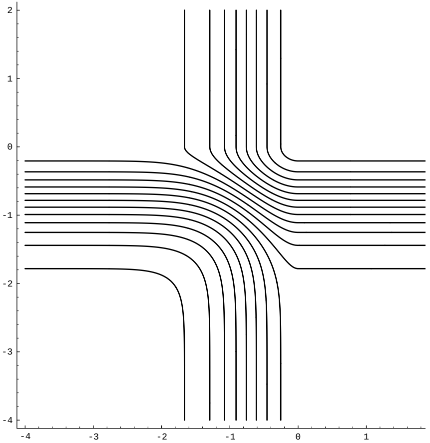


Figure: 20 equally-spaced contours of H_α, which increases from 0 in the bottom-left to 1 in the top-right. Note that H_α is increasing and that sublevels of small enough values are convex.

Bounds Using Orthants

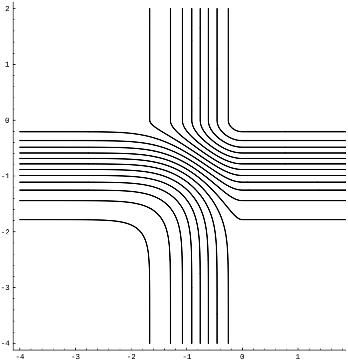
Since H_α is increasing in each of its K arguments and the K random variables $\langle f | A_k \rangle$ are independent, one bound on $\mu[H_\alpha(Y) \leq H_\alpha(-\alpha)]$ is provided as follows: fix $\varepsilon > 0$, choose any $\varepsilon_1, \dots, \varepsilon_K > 0$ such that $1 - \varepsilon = \prod_{k=1}^{K} (1 - \varepsilon_k)$, and set

$$\alpha_k := \mathcal{D}[f | A_k] \sqrt{\frac{\log(1/\varepsilon_k)}{2m_k}}.$$

Then

$$\begin{aligned} \mu\big[H_\alpha(Y) \geq H_\alpha(-\alpha)\big] &\geq \prod_{k=1}^{K} \mu[Y_k \geq -\alpha_k] \\ &\geq \prod_{k=1}^{K} (1 - \varepsilon_k) \\ &= 1 - \varepsilon. \end{aligned}$$

The Problem with Orthants. . .



- The problem with the bound on the previous slide is that for even moderately large K, ε_k must be tiny in order to make ε small enough. It then follows that m_k must be large in order to make the margin hit α_k acceptably small.
- Geometrically, this can be seen as a consequence of using K-dimensional orthants to estimate the measure of a set: viewed from their vertices, high-dimensional orthants look very "narrow".
- Half-spaces are much better, dimensionally speaking, since they always fill half the "field of view".

A Bound on the Measure of a Half-Space

Denote by $\mathbb{H}_{p,\nu}$ the closed half-space in $\mathbb{R}^K$ that has p on its boundary and ν as an outward-pointing normal:

$$\mathbb{H}_{p,\nu} := \left\{ y \in \mathbb{R}^K \,\middle|\, \nu \cdot y \leq \nu \cdot p \right\}.$$

Since $\mathbb{E}[\nu \cdot Y] = 0$, application of McDiarmid's inequality yields that

$$\mu[Y \in \mathbb{H}_{p,\nu}] \leq \exp\left(-2(\nu \cdot p)_-^2 \middle/ \sum_{k=1}^{K} \frac{|\nu_k|^2}{m_k} \mathcal{D}[f|A_k]^2 \right).$$

Hence, for any $S \subseteq \mathbb{R}^K$,

$$\mu[Y \in S] \leq \inf \left\{ \exp\left(- \frac{2(\nu \cdot p)_-^2}{\sum_{k=1}^{K} \frac{|\nu_k|^2}{m_k} \mathcal{D}[f|A_k]^2} \right) \,\middle|\, \begin{array}{c} p \in \mathbb{R}^K \text{ and } \nu \in \mathbb{R}^K \\ \text{such that } S \subseteq \mathbb{H}_{p,\nu} \end{array} \right\}.$$

Consequences for H_α

Suppose it is known *a priori* that $H_\alpha(-\alpha)$ is small enough that the sublevel set $H_\alpha^{-1}([0, H_\alpha(-\alpha)])$ is convex. Then, applying the inequality from the previous slide with $p = -\alpha$ and $\nu = \nabla H_\alpha(-\alpha)$ yields that

$$\mu\big[H_\alpha(Y) \leq H_\alpha(-\alpha)\big] \leq \exp\left(- \frac{2(\nabla H_\alpha(-\alpha) \cdot \alpha)_+^2}{\sum_{k=1}^{K} \frac{|\partial_k H_\alpha(-\alpha)|^2}{m_k} \mathcal{D}[f|A_k]^2} \right).$$

Note:

$$\partial_k H_\alpha(-\alpha) = \frac{4\mu(A_k)(\mathbb{E}[f|A_k] - \theta)_+}{\mathcal{D}[f|A_k]^2} \exp\left(- \frac{2(\mathbb{E}[f|A_k] - \theta)_+^2}{\mathcal{D}[f|A_k]^2} \right) \geq 0.$$

Note also that, by assumption, $\mathbb{E}[f|A_k]$ is unknown, so in practice one takes a supremum over known ranges of values for $\mathbb{E}[f|A_k]$.

$K = 2$, $m_1 = m_2 = 5$	$\varepsilon_1 = \varepsilon_2 = 1\%$	
Upper bounds on the probability of failure (*i.e.* non-perforation, $[f = 0]$)		
If inputs uniformly dist.	3.7%	
Exact local means: $\overline{\mu_{\mathcal{P}}}[f = 0]$	33%	
Empirical local means: $H_\alpha(Y)$	54%	
Confidence levels (*i.e.* upper bounds on $\mu\big[H_\alpha(Y) \leq \overline{\mu_{\mathcal{P}}}[f = 0]\big]$)		
Orthant method	2%	
Half-space method		
Means known exactly	0.9%	
Means known to within $\pm 1\,\mathrm{mm}^2$	0.9%	
Means known to within $\pm 5\,\mathrm{mm}^2$	1.0%	

$K = 2$, $m_1 = m_2 = 5$	$\varepsilon_1 = \varepsilon_2 = 1\%$	$\varepsilon_1 = \varepsilon_2 = 0.1\%$
Upper bounds on the probability of failure (*i.e.* non-perforation, $[f = 0]$)		
If inputs uniformly dist.	3.7%	
Exact local means: $\overline{\mu_{\mathcal{P}}}[f = 0]$	33%	
Empirical local means: $H_\alpha(Y)$	54%	58%
Confidence levels (*i.e.* upper bounds on $\mu\left[H_\alpha(Y) \leq \overline{\mu_{\mathcal{P}}}[f = 0]\right]$)		
Orthant method	2%	0.20%
Half-space method		
Means known exactly	0.9%	0.09%
Means known to within $\pm 1\,\mathrm{mm}^2$	0.9%	0.09%
Means known to within $\pm 5\,\mathrm{mm}^2$	1.0%	0.10%

Scaling of Confidence Levels with K

This example leads us to consider the very different scaling properties of the orthant and half-space methods, provided sample sizes $m_1, \dots, m_K$ are chosen appropriately.

Proposition

Suppose that the same level of confidence $1 - \varepsilon_0$ is required for each local mean $\mathbb{E}[f|A_k]$, $k = 1, \dots, K$. Choose sample sizes m_k such that

$$\sqrt{m_k} \propto \partial_k H_\alpha(-\alpha) \mathcal{D}[f|A_k].$$

Then the confidence levels for H_α are given by:

$$\begin{aligned} \textit{half-space method:} \quad & \mu\big[H_\alpha(Y) \geq H_\alpha(-\alpha)\big] \geq 1 - \varepsilon_0^K; \\ \textit{orthant method:} \quad & \mu\big[H_\alpha(Y) \geq H_\alpha(-\alpha)\big] \geq (1 - \varepsilon_0)^K. \end{aligned}$$

Half-Space / Chernoff Concentration

- The use of half-spaces exploits the fact that, in a probability normed vector space $\mathcal{V}$, a convex set C that does not contain the centre of mass has small measure — exponentially small with respect to its distance from the centre of mass.
- Hence, a quasiconvex function f on $\mathcal{V}$ is unlikely to assume values below its value at the centre of mass.
- This differs from concentration/deviation results in the literature in two ways:
  - there are no smoothness assumptions on f;
  - the result is a one-sided concentration about the value of f at the centre of mass, not about $\mathbb{E}[f]$.
- We believe that results of this type indicate a deeper connection between concentration-of-measure phenomena and large deviations principles.

Conclusions

In situations where failure is a rare event but McDiarmid diameters can be computed:

- McDiarmid's inequality offers a rigorous upper bound on the probability of failure (certification criterion);
- partitioning offers a way to obtain arbitrarily sharp upper bounds on the probability of failure, at the cost of further diameter calculations;
- this can be done in ways that avoid the naïve curse of dimension;
- half-space methods provide confidence bounds in which high-cardinality partitions are a help, not a hindrance.

Outlook

- It is not necessary to assume that the components of $X = (X_1, \dots, X_n)$ are independent and that the partition elements are rectangles: in the general situation, resort to martingale inequalities.
- The μ and f to which CORPUS is applied may be surrogates for the real μ' and f' on which the probability of failure upper bound will be calculated (perhaps using sampling) — can the approximation error be controlled?
- Does it make sense to ask for the "optimal" partition of a given cardinality? of a given mesh size?
- How can these methods be extended to handle noisy / imperfectly observed response functions f?

Bibliography & Acknowledgements

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