6.01

# Lecture 9: Probabilistic Reasoning

Adam Hartz (hz@mit.edu)

Notes			

### Overview and Perspective

Focus on  $\ensuremath{\text{key}}$  concepts with  $\ensuremath{\text{explicit}}$  connections



in an **authentic context** with overarching theme: **Modular Design of Complex Systems** 



Controlling complexity:

Primitives, Combinations, Abstractions, and Common Patterns

Lintro to EECS1 Lecture 9 (slide 2)

Notes

### Module 3: Probabilistic Reasoning

Modeling uncertainty and desiging robust systems

**Topics:** Subjective Probability, Markov Processes, Bayesian Inference

Lab Exercises:

• Localization: Find location in known hallway

Notes			
-			
-			

Intro to EECS I Lecture 9 (

8 Apr 201

### **Probability Theory**

Probability theory provides a framework for:

- Modeling and reasoning about uncertainty

  - Making precise statements about uncertain situations
     Drawing reliable inferences from unreliable observations
- Designing systems that are robust to uncertainty

-		

Notes

#### Check Yourself!

If a test to detect a disease whose prevalence is  $1/1000\ \text{has}$  a false positive rate of 5% (and a false negative rate of 0%). Patient 0 is found to have received a positive result on the test. What is the chance that Patient 0 actually has the disease, assuming you know nothing about the person's  $% \left( 1\right) =\left( 1\right) \left( 1\right) \left($ symptoms or signs?

Which of the following is closest to the right answer?

- 0.1%
- 1. 2%
- 2. 5%
- 3. 10%
- 4. 50%
- **5**. 95%

Notes			

Probability	Review:	Basics

 $\textbf{Probability} \colon \ \mathsf{Likelihood} \ \ \mathsf{of} \ \ \mathsf{an} \ \ \mathsf{event} \ \ \mathsf{occurring} \colon \ \Pr(A=a)$ 

**Distribution**: Function from elements a in domain A to probabilities:  $\Pr(A): a \to p$ 

Conditional Probability: Likelihood of an event occuring, after knowing that some other event occurred:  $\Pr(A=a|B=b)$ 

Conditional Distribution: Function from elements  $\boldsymbol{b}$  in domain  $\boldsymbol{B}$  to distributions over  $A \colon \Pr(A|B) : b \to (a \to p)$ 

**Joint Probability**: Probability of two events happening: Pr(A = a, B = b)

 $\label{eq:continuous} \textbf{Joint Distribution} : \mbox{Function from elements } (a,b) \mbox{ in domain } (A,B) \mbox{ to}$ probabilities:  $\Pr(A,B):(a,b)\to p$ 

Notes			
-			
-			

### Probability: Events

Probabilities (representing a likelihood of occurrence) are assigned to  ${\bf events},$  which are possible outcomes of an experiment.

Example: Flip three coins in succession. Possible events:

- head, head, head
- head, tail, head
- one head and two tails
- first toss was a head

There are eight atomic (finest grain) events: HHH, HHT, HTH, HTT, THH, THT, TTH, TTT

Atomic events are **mutually exclusive** (only one can happen). Set of all atomic events is **collectively exhaustive** (cover all cases). Set of all possible atomic events is called the **sample space** U.

Lecture 9 (slide

8 Apr 20

Notes

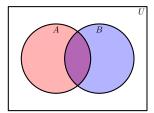
Notes

## Probability Theory: Axioms of Probability

A probability  $\Pr(A)$  is assigned to each atomic event A.

The probabilities assigned to events must obey three axioms:

- $\Pr(A) \ge 0$  for all events A
- $\Pr(U) = 1$
- $Pr(A \cup B) = Pr(A) + Pr(B) Pr(A \cap B)$



0.01 Intro to EECS

Lecture 9 (slide 8

8 Apr 20

### Conditional Probability

Often times, the probability of an event happening changes depending on whether or not another event happened. The events are, generally, dependent.

Conditional probability:

 $Pr(A \mid B)$ 

This probability (pronounced "the probability of A given B") represents the probability of event A happening, given that event B happened.

Notes			

.01 Intro to EECS I

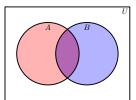
Lecture 9 (slide 9)

B Apr 201

### Conditional Probability

Here we  ${\it know}$  that  ${\it B}$  happened, so we can throw everything else away ("condition" on  ${\it B}).$ 

Conditioning on B restricts the sample space (which was U) to B:





 ${\cal U}$  has shrunk to  ${\cal B}$ 

$$\Pr(A \mid B) = \frac{\Pr(A, B)}{\Pr(B)}$$

$$\Pr(A,B) = \Pr(B) \times \Pr(A \ | \ B)$$

Lecture 9 (slide

8 Apr 20

Notes

Notes

#### Check Yourself!

Ben Bitdiddle applied to both MIT and Harvard. Ben believes that his probability of being accepted at MIT is 0.10, at Harvard is 0.06, and at neither is 0.843.

What is the probability that Ben will get accepted to either  $\ensuremath{\mathsf{MIT}}$  or Harvard but not both?

intro to EECS I Lecture 9 (sli

# Check Yourself

Consider a sequence of two songs on the radio.

Let  $B_1$  be the event that the first song is by Ariana Grande. Let  $B_2$  be the event that the second song is by Ariana Grande.

 $Pr(B_1) = 0.7$ 

 $\Pr(B_2 \mid \overline{B_1}) = 0.9$ 

 $Pr(B_2 \mid B_1) = 0.8$ 

What is the probability that the second song is by Ariana Grande?

Notes

\_

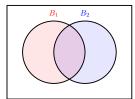
0.01 Intro to EECS

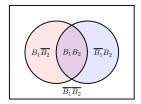
Lecture 9 (slide 12)

3 Apr 201

### Symmetry

Decision trees are sequential, but set representation is symmetric.





We could compute the joint probability two ways:  $\Pr(B_1,B_2) = \Pr(B_1)\Pr(B_2 \mid B_1) = \Pr(B_2)\Pr(B_1 \mid B_2)$ 

Notes \_\_\_\_\_\_

# Inverse Probability

We can compute the joint probability  $\Pr(B_1,B_2)$  in two ways:

$$Pr(B_1, B_2) = Pr(B_1) Pr(B_2 \mid B_1) = Pr(B_2) Pr(B_1 \mid B_2)$$

A slight manipulation gives us Bayes' Theorem:

$$\Pr(B_1 \mid B_2) = \frac{\Pr(B_1) \Pr(B_2 \mid B_1)}{\Pr(B_2)}$$

Allows for  ${\it anti-sequential}$  reasoning: infer causes from effects, or infer future events from past information.

Notes

### Check Yourself

Consider a sequence of two songs on the radio.

Let  $B_1$  be the event that the first song is by Ariana Grande. Let  $B_2$  be the event that the second song is by Ariana Grande.

$$Pr(B_1) = 0.7$$

$$\Pr(B_2 \mid \overline{B_1}) = 0.9$$

$$Pr(B_2 \mid B_1) = 0.8$$

You tune in during the second song, and it turns out that it is *not* by Ariana Grande. What is the probability that the song before it *was* by Ariana Grande?

Notes			

.01 Intro to EECS I Lecture 9 (slide 15)

### Bayes' Theorem

"Inverse Probability:" infer causes from effects, or infer future events from past information  $% \left( 1\right) =\left( 1\right) \left( 1\right)$ 

Basic idea: combine old belief with evidence to generate a new belief.

$$\Pr(H = h \mid E = e) = \frac{\Pr(E = e \mid H = h) \cdot \Pr(H = h)}{\Pr(E = e)}$$

Pr(H = h): how likely was the hypothesis h?

 $\Pr(E=e\mid H=h)$ : how well is the evidence e supported by h?

 $\Pr(E=e)\text{: normalizing factor}$ 

 $\Pr(H = h \mid E = e)$ : how likely is h after the evidence?

Lecture 9 (slide 16

8 Apr 20

Notes

Notes

## Dice Game

I have 6 dice:

- 4-sided
- 6-sided
- 8-sided
- 10-sided
- 12-sided
- 20-sided

I pick one at random and roll it, telling you what number I roll. Can you figure out which die I picked?

6.01 Intro to EECS

Lecture 9 (slide 17

8 Apr 20

# Check Yourself!

I pick a die and roll a "5". Obviously, this means the probability that I was rolling the 4-sided die, call it  $p_4=\Pr(\text{die}=4\mid\text{observe 5}),$  is 0.

What can be said about the updated probabilities of the other dice?

- 1.  $p_6 < p_8 < p_{10} < p_{12} < p_{20}$
- 2.  $p_6 = p_8 = p_{10} = p_{12} = p_{20}$
- 3.  $p_6 > p_8 > p_{10} > p_{12} > p_{20}$
- 4. None of the above

Notes		
-		

ntro to EECS I Lecture 9

8 Apr 201

Check Yourself!	
Say I roll a very large number $n$ of 5's in a row, starting from uniform. What happens to the belief distribution over dice as $n \to \infty$ ?  1. It becomes uniform over all states but 4.	Notes
2. One state has probability $\rightarrow$ 1.	
3. None of the above	
ro to EECS 1 Lecture 9 (slide 19) 8 Apr 2019	
Check Yourself!	
If a test to detect a disease whose prevalence is 1/1000 has a false positive	Notes
rate of 5% (and a false negative rate of 0%). Patient 0 is found to have received a positive result on the test. What is the chance that Patient 0	
actually has the disease, assuming you know nothing about the person's symptoms or signs?	
Which of the fellowing is glosset to the right convers	
Which of the following is closest to the right answer?  0. 1%	
1. 2% 2. 5%	
3. 10% 4. 50%	
5. 95%	
ro to EECS I Lecture 9 (slide 20) 8 Apr 2019	
Check Yourself!	
There are two people: Pat and Cameron.	Notes
What is the probability that Pat is older than Cameron?	

Intro to EECS I Lecture 9 (slide 21) 8

6.01 Int

Subjective Probability	
In this view, probabilities represent not frequencies of occurrance, but our <i>belief</i> about the likelihood of occurrance, and our uncertainty about the results.	Notes
Same math! Different interpretation!	
.01 Intro to EECS 1 Lecture 9 (slide 22) 8 Apr 201	
	_
Game 2	
I have one cup with 4 dice in it. Each die is either red or white. Your goal is	Notes
to guess how many red dice are in the cup.	
01 Intro to EECS I Lecture 9 (slide 23) 8 Apr 201	
Check Yourself!	
What is a good initial belief about the number of red dice in the cup?	Notes
.01 Intro to EECS I Lecture 9 (slide 24) 8 Apr 201:	9

### Thinking About the Game Quantitatively

Which dice could be in the cup?

- ▶ 4 white
- ▶ 3 white + 1 red
- ▶ 2 white + 2 red
- ▶ 1 white + 3 red
- ▶ 4 red

How likely are these?

Assume equally likely (for lack of a better assumption).

n = # of red	0	1	2	3	4
Pr(N = n)	1/5	1/5	1/5	1/5	1/5

Notes			
-			

### Incorporating New Information

Assume that, before the bet, Adam pulls a random die, tells you its color, and returns it.

To update the belief based on this information, which of the following must be applied?

- 1. Bayes' Theorem
- 2. Total Probability
- 3. Something Else

N	Of	te	S

### Incorporating New Information

Assume that, before the bet, Adam pulls a random die, tells you it is **red**, and returns it.

What should your belief be now? We need to update the belief!

n=# of red	0	1	2	3	4			
Pr(N = n)	1/5	1/5	1/5	1/5	1/5			
"Prior" Belief								

Pr(N = n)	1/5	1/5	1/5	1/5	1/5
$\Pr(E = \text{red} \mid N = n)$	0	1/4	1/2	3/4	1
Pr(E = red, N = n)	0	1/20	2/20	3/20	4/20
$\Pr(N = n \mid E = \text{red})$	0	1/10	2/10	3/10	4/10

"Posterior" Belief

Notes			

### Incorporating More New Information

After telling you about the red die, Adam pulls another random die, tells you it is  ${\bf red},$  and returns it.

We need to update the state belief again! Previous "posterior" belief is now the "prior" belief.

n=# of red	0	1	2	3	4			
Pr(N = n)	0	1/10	2/10	3/10	4/10			
"Prior" Belief								

n = # of red	0	1	2	3	4
$\Pr(E = \text{red} \mid N = n)$	0	1/4	1/2	3/4	1
Pr(E = red, N = n)	0	1/40	4/40	9/40	16/40
$Pr(N = n \mid E = red)$	0	1/30	4/30	9/30	16/30

"Posterior" Belief

Notes

## Bayesian Estimation

Using observations to improve on initial guess.

We started with no information:

n = # of red	0	1	2	3	4
Pr(N = n)	1/5	1/5	1/5	1/5	1/5

Then we "observed" a red die:

n=# of red	0	1	2	3	4
Pr(N = n)	0	1/10	2/10	3/10	4/10

Then we "observed" a red die:

n=# of red	0	1	2	3	4
Pr(N = n)	0	1/30	4/30	9/30	16/30

21 Intro to EECS I Lecture 9 (slide 29) 8 Apr 20

Notes			

### Alternate Observations

- Pat is sneaky and wants to cheat you. Pat always says:
  - "red" if a white die was drawn
  - "white" if a red die was drawn
- Cameron can't tell the difference between white and red; and so always chooses to tell you a color at random.

We are aware of these predispositions!

Notes			
-			
-			

5.01 Intro to EECS I Lecture 9 (slide 30)

#### Check Yourself!

Pat always says:

- "red" if a white die was drawn
- "white" if a red die was drawn

How does our belief state change when Pat tells us that a white die was drawn?

- 1. Same as if Adam (honest) told us red was drawn.
- 2. Same as if Adam (honest) told us white was drawn.
- 3. It does not change.
- 4. None of the above.

Lecture 9 (slide )

8 Apr 20

Notes

#### Check Yourself!

Cameron says any of the colors with probability 1/2, regardless of what was actually drawn.

How does our belief state change when Cameron tells us that a white die was drawn?

- 1. Same as if Adam (honest) told us red was drawn.
- 2. Same as if Adam (honest) told us white was drawn.
- 3. It does not change.
- 4. None of the above.

5.01 Intro to EECS

Lecture 9 (slide 32

8 Apr 20

#### Labs

Bayesian estimation of robot location. Model the location of the robot as a Markov process Estimate the location of the robot from sonar observations

- SL09: Practice with Theoretical "Robot in Hallway"
- DL10: "Robot in Hallway" in Python
- Lec11: Bayesian State Estimation, Probabilistic Modeling
- SL11: Localization and Parking 1
- DL11: Localization and Parking 2

Netes	
Notes	
Notes	

5.01 Intro to EECS I Lecture 9 (slide 33)