

Stochastic Simulation

- **Idea:** probabilities \leftrightarrow samples
- Get probabilities from samples:

| X | <i>count</i> |
|--------------|--------------|
| x_1 | n_1 |
| \vdots | \vdots |
| x_k | n_k |
| <i>total</i> | m |

 \leftrightarrow

| X | <i>probability</i> |
|----------|--------------------|
| x_1 | n_1/m |
| \vdots | \vdots |
| x_k | n_k/m |

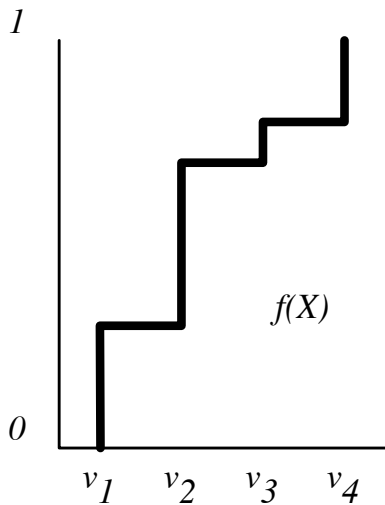
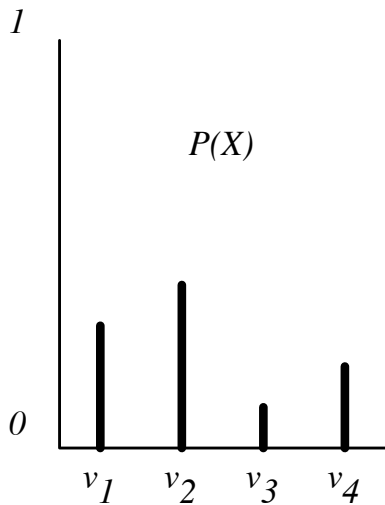
- If we could sample from a variables (posterior) probability, we could estimate its (posterior) probability.

Generating samples from a distribution

For a variable X with a discrete domain or a (one-dimensional) real domain:

- Totally order the values of the domain of X .
- Generate the cumulative probability distribution:
 $f(x) = P(X \leq x)$.
- Select a value y uniformly in the range $[0, 1]$.
- Select the x such that $f(x) = y$.

Cumulative Distribution



Forward sampling in a belief network

- Sample the variables one at a time; sample parents of X before you sample X .
- Given values for the parents of X , sample from the probability of X given its parents.

Rejection Sampling

- To estimate a posterior probability given evidence $Y_1 = v_1 \wedge \dots \wedge Y_j = v_j$:
- If, for any i , a sample assigns Y_i to any value other than v_i reject that sample.
- The non-rejected samples are distributed according to the posterior probability.

Importance Sampling

- If we can compute $P(\textit{evidence}|\textit{sample})$ we can weight the (partial) sample by this value.
- To get the posterior probability, we do a weighted sum over the samples; weighting each sample by its probability.
- We don't need to sample all of the variables as long as we weight each sample appropriately.
- We thus mix exact inference with sampling.

Particle Filtering

- Suppose the evidence is $e_1 \wedge e_2$
$$P(e_1 \wedge e_2 | sample) = P(e_1 | sample)P(e_2 | e_1 \wedge sample)$$
- After computing $P(e_1 | sample)$, we may know the sample will have an extremely small probability.
- Idea: we use lots of samples: “particles”. A particle is a sample on some of the variables.
- Based on $P(e_1 | sample)$, we resample the set of particles. We select from the particles according to their weight.
- Some particles may be duplicated, some may be removed.