Combining Interval and Probabilistic Uncertainty in Engineering Applications

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Part I
Introduction
1. Need for Data Processing

- One of the main objectives of science is to predict future values \( y \) of physical quantities:
  - in meteorology, we need to predict future weather;
  - in airplane control, we need to predict the location and the velocity of the plane under current control.

- To make this prediction:
  - we need to know the relation \( y = f(x_1, \ldots, x_n) \) between \( y \) and related quantities \( x_1, \ldots, x_n \);
  - then, we measure or estimate \( x_1, \ldots, x_n \);
  - finally, we use the results \( \tilde{x}_i \) of measurement (or estimation) to compute an estimate

\[
\tilde{y} = f(\tilde{x}_1, \ldots, \tilde{x}_n).
\]

- This computation of \( \tilde{y} \) is an important case of data processing.
2. Need to Take Uncertainty Into Account When Processing Data

- Measurement are never absolutely accurate: in general,
  \[ \Delta x_i \overset{\text{def}}{=} \tilde{x}_i - x_i \neq 0. \]

- As a result, the estimate \( \tilde{y} = f(\tilde{x}_1, \ldots, \tilde{x}_n) \) is, in general, different from the ideal value \( y = f(x_1, \ldots, x_n) \).

- To estimate the accuracy \( \Delta y \overset{\text{def}}{=} \tilde{y} - y \), we need to have some information about the measurement errors \( \Delta x_i \).

- Traditional engineering approach assumes that we know the probability distribution of each \( \Delta x_i \).

- Often, \( \Delta x_i \sim N(0, \sigma_i) \), and different \( \Delta x_i \) are assumed to be independent.

- In such situations, our goal is to find the probability distribution for \( \Delta y \).
3. Cases of Interval and Fuzzy Uncertainty

- Often, we only know the upper bound $\Delta_i$: $|\Delta x_i| \leq \Delta_i$.
- Then, the only information about the $x_i$ is that
  \[ x_i \in x_i \overset{\text{def}}{=} [\tilde{x}_i - \Delta_i, \tilde{x}_i + \Delta_i]. \]
- Different $x_i \in x_i$ lead, in general, to different
  \[ y = f(x_1, \ldots, x_n). \]
- We want to find the range $y$ of possible values of $y$:
  \[ y = \{ f(x_1, \ldots, x_n) : x_1 \in x_1, \ldots, x_n \in x_n \}. \]
- To gauge the accuracy of expert estimates, it is reasonable to use fuzzy techniques, i.e., to describe:
  - for each possible value $x_i$,
  - the degree $\mu_i(x_i)$ to which $x_i$ is possible.
4. Measurement and Estimation Inaccuracies Are Usually Small

- In many practical situations, the measurement and estimation inaccuracies $\Delta x_i$ are relatively small.

- Then, we can safely ignore terms which are quadratic (or of higher order) in terms of $\Delta x_i$:

$$\Delta y = \tilde{y} - y = f(\tilde{x}_1, \ldots, \tilde{x}_n) - f(\tilde{x}_1 - \Delta x_1, \ldots, \tilde{x}_n - \Delta x_n) = \sum_{i=1}^{n} c_i \cdot \Delta x_i,$$

where $c_i = \frac{\partial f}{\partial x_i}$.

- If needed, the derivative can be estimated by numerical differentiation:

$$c_i \approx \frac{f(\tilde{x}_1, \ldots, \tilde{x}_{i-1}, \tilde{x}_i + h, \tilde{x}_{i+1}, \ldots, \tilde{x}_n) - \tilde{y}}{h}.$$
5. Case of Interval Uncertainty

- Let us consider the case when $\Delta y = \sum_{i=1}^{n} c_i \cdot \Delta x_i$.

- In this case, $y = [\tilde{y} - \Delta, \tilde{y} + \Delta]$, where $\Delta = \sum_{i=1}^{n} |c_i| \cdot \Delta_i$.

- Sometimes, we have explicit expressions or efficient algorithms for the partial derivatives $c_i$.

- Often, however, we use proprietary software in our computations.

- Then, we cannot use differentiation formulas, but we can use numerical differentiation.

- **Problem:** We need $n + 1$ calls to $f$, to compute $\tilde{y}$ and $n$ values $c_i$.

- When $f$ is time-consuming and $n$ is large, this takes too long.
6. A Faster Method: Cauchy-Based Monte-Carlo

• Idea: use Cauchy distribution $\rho_{\Delta}(x) = \frac{\Delta}{\pi} \cdot \frac{1}{1 + x^2/\Delta^2}$.

• Why: when $\Delta x_i \sim \rho_{\Delta_i}(x)$ are indep., then
  \[ \Delta y = \sum_{i=1}^{n} c_i \cdot \Delta x_i \sim \rho_{\Delta}(x), \text{ with } \Delta = \sum_{i=1}^{n} |c_i| \cdot \Delta_i. \]

• Thus, we simulate $\Delta x_i^{(k)} \sim \rho_{\Delta_i}(x)$; then,
  \[ \Delta y^{(k)} \overset{\text{def}}{=} \bar{y} - f(\bar{x}_1 - \Delta x_1^{(k)}, \ldots) \sim \rho_{\Delta}(x). \]

• Maximum Likelihood method can estimate $\Delta$:
  \[ \prod_{k=1}^{N} \rho_{\Delta}(\Delta y^{(k)}) \rightarrow \text{max}, \text{ so } \sum_{k=1}^{N} \frac{1}{1 + (\Delta y^{(k)})^2/\Delta^2} = \frac{N}{2}. \]

• To find $\Delta$ from this equation, we can use, e.g., the bisection method for $\underline{\Delta} = 0$ and $\overline{\Delta} = \max_{1 \leq k \leq N} |\Delta y^{(k)}|$. 
7. Monte-Carlo: Successes and Limitations

- **Fact:** for Monte-Carlo, accuracy is \( \varepsilon \sim 1/\sqrt{N} \).
- **Good news:** the number \( N \) of calls to \( f \) depends only the desired accuracy \( \varepsilon \).
- **Example:** to find \( \Delta \) with accuracy 20% and certainty 95%, we need \( N = 200 \) iterations.
- **Limitation:** this method is *not realistic*; indeed:
  - we know that \( \Delta x_i \) is *inside* \([−\Delta, \Delta]\), but
  - Cauchy-distributed variable has a high probability to be *outside* this interval.
- **Natural question:** is it a limitation of our method, or of a problem itself?
8. Fuzzy Case: A Problem

- **Given**: an algorithm \( y = f(x_1, \ldots, x_n) \) and \( n \) fuzzy numbers \( \mu_i(x_i) \).
- **Compute**: 
  \[
  \mu(y) = \max_{x_1, \ldots, x_n : f(x_1, \ldots, x_n) = y} \min(\mu_1(x_1), \ldots, \mu_n(x_n)).
  \]
- **Motivation**: \( y \) is a possible value of \( Y \leftrightarrow \exists x_1, \ldots, x_n \) s.t. each \( x_i \) is a possible value of \( X_i \) and \( f(x_1, \ldots, x_n) = y \).
- **Details**: “and” is min, \( \exists \) (“or”) is max, hence
  \[
  \mu(y) = \max_{x_1, \ldots, x_n} \min(\mu_1(x_1), \ldots, \mu_n(x_n), t(\mathcal{f}(x_1, \ldots, x_n) = y)),
  \]
  where \( t(\text{true}) = 1 \) and \( t(\text{false}) = 0 \).
9. Fuzzy Case: Reduction to Interval Computations

- **Given:** an algorithm \( y = f(x_1, \ldots, x_n) \) and \( n \) fuzzy numbers \( X_i \) described by membership functions \( \mu_i(x_i) \).
- **Compute:** \( Y = f(X_1, \ldots, X_n) \), where \( Y \) is defined by Zadeh’s extension principle:
  \[
  \mu(y) = \max_{x_1, \ldots, x_n : f(x_1, \ldots, x_n) = y} \min(\mu_1(x_1), \ldots, \mu_n(x_n)).
  \]
- **Idea:** represent each \( X_i \) by its \( \alpha \)-cuts
  \[
  X_i(\alpha) = \{ x_i : \mu_i(x_i) \geq \alpha \}.
  \]
- **Advantage:** for continuous \( f \), for every \( \alpha \), we have
  \[
  Y(\alpha) = f(X_1(\alpha), \ldots, X_n(\alpha)).
  \]
- **Resulting algorithm:** for \( \alpha = 0, 0.1, 0.2, \ldots, 1 \) apply interval computations techniques to compute \( Y(\alpha) \).
10. **Open Problems**

- In engineering applications, we want methods for estimating uncertainty which are:
  - *accurate* – this is most important in most engineering applications;
  - *fast*: this is important in some engineering applications where we need real-time computations,
  - *understandable* to engineers – otherwise, engineers will be reluctant to use them, and
  - sufficiently *general* – so that they can be applied in all kinds of situations.

- It is thus desirable to design more accurate, faster, more understandable, and/or more general methods.
11. What We Do in This Thesis

• First, we show how to make the current methods more accurate.

• Then, we show how to make these methods faster.

• After that, we show how to make these methods more understandable to engineers.

• Finally, we analyze how to make these methods more general.

• We also describe remaining open problems and our plan for future work.
Part II

How to Get More Accurate Estimates – by Properly Taking Model Inaccuracy into Account
12. Linearization-Based Algorithm: Reminder

- **We know:** an algorithm $f(x_1, \ldots, x_n)$ and values $\tilde{y}_i$ and $\Delta_i$.
- **We need to find:** the range of values $f(x_1, \ldots, x_n)$ when $x_i \in [\tilde{x}_i - \Delta_i, \tilde{x}_i + \Delta_i]$.
- **Algorithm:**
  
  1) first, we compute $\tilde{y} = f(\tilde{x}_1, \ldots, \tilde{x}_n)$;
  2) then, for each $i$ from 1 to $n$, we compute
     
     $y_i = f(\tilde{x}_1, \ldots, \tilde{x}_{i-1}, \tilde{x}_i + \Delta_i, \tilde{x}_{i+1}, \ldots, \tilde{x}_n)$;
  3) after that, we compute $\bar{y} = \tilde{y} + \sum_{i=1}^{n} |y_i - \tilde{y}|$ and
     
     $\underline{y} = \tilde{y} - \sum_{i=1}^{n} |y_i - \tilde{y}|$. 
13. Taking Model Inaccuracy into Account

- We rarely know the exact dependence \( y = f(x_1, \ldots, x_n) \).
- We have an approx. model \( F(x_1, \ldots, x_n) \) w/known accuracy \( \varepsilon: |F(x_1, \ldots, x_n) - f(x_1, \ldots, x_n)| \leq \varepsilon \).
- We know: an algorithm \( F(x_1, \ldots, x_n) \), accuracy \( \varepsilon \), values \( \tilde{x}_i \) and \( \Delta_i \).
- Find: the range \( \{f(x_1, \ldots, x_n) : x_i \in [\tilde{x}_i - \Delta_i, \tilde{x}_i + \Delta_i]\} \).
- If we use the approximate model in our estimate, we get \( \bar{Y} = \tilde{Y} + \sum_{i=1}^{n} |Y_i - \tilde{Y}| \).
- Here, \( |\tilde{Y} - \tilde{y}| \leq \varepsilon \) and \( |Y_i - y_i| \leq \varepsilon \), so \( |\bar{y} - \bar{Y}| \leq (2n + 1) \cdot \varepsilon \).
- Thus, we arrive at the following algorithm.
14. Resulting Algorithm

- **We know:** an algorithm $F(x_1, \ldots, x_n)$, accuracy $\varepsilon$, values $\tilde{x}_i$ and $\Delta_i$.
- **Find:** the range $\{f(x_1, \ldots, x_n) : x_i \in [\tilde{x}_i - \Delta_i, \tilde{x}_i + \Delta_i]\}$.
- **Algorithm:**
  1) compute $\tilde{Y} = Y(\tilde{x}_1, \ldots, \tilde{x}_n)$ and
     \[Y_i = F(\tilde{x}_1, \ldots, \tilde{x}_{i-1}, \tilde{x}_i + \Delta_i, \tilde{x}_{i+1}, \ldots, \tilde{x}_n).\]
  2) compute $B = \tilde{Y} + \sum_{i=1}^{n} |Y_i - \tilde{Y}| + (2n + 1) \cdot \varepsilon$ and
     \[\overline{B} = \tilde{Y} - \sum_{i=1}^{n} |Y_i - \tilde{Y}| - (2n + 1) \cdot \varepsilon.\]
- **Problem:** when $n$ is large, then, even for reasonably small inaccuracy $\varepsilon$, the value $(2n + 1) \cdot \varepsilon$ is large.
- **What we do:** we show how we can get better estimates for $\overline{y}$.
15. How to Get Better Estimates: Idea

• One possible source of model inaccuracy is discretization (e.g., FEM).

• When we select a different combination of parameters, we get an unrelated value of inaccuracy.

• So, let’s consider approx. errors \( \Delta y \overset{\text{def}}{=} F(x_1, \ldots, x_n) - f(x_1, \ldots, x_n) \) as independent random variables.

• What is a probability distribution for these random variables? We know that \( \Delta y \in [-\varepsilon, \varepsilon] \).

• We do not have any reason to assume that some values from this interval are more probable than others.

• So, it is reasonable to assume that all the values are equally probable: a uniform distribution.

• For this uniform distribution, the mean is 0, and the standard deviation is \( \sigma = \frac{\varepsilon}{\sqrt{3}} \).
16. How to Get a Better Estimate for $\tilde{y}$

- In our main algorithm, we apply the computational model $F$ to $n + 1$ different tuples.

- Let's also compute $M \overset{\text{def}}{=} F(\tilde{x}_1 - \Delta_1, \ldots, \tilde{x}_n - \Delta_n)$.

- In linearized case, $\tilde{y} + \sum_{i=1}^{n} y_i + m = (n + 2) \cdot \tilde{y}$, so $\tilde{y} = \frac{1}{n + 2} \cdot \left( \tilde{y} + \sum_{i=1}^{n} y_i + m \right)$, and we can estimate $\tilde{y}$ as

$$\tilde{Y}_{\text{new}} = \frac{1}{n + 2} \cdot \left( \tilde{Y} + \sum_{i=1}^{n} Y_i + m \right).$$

- Here, $\Delta \tilde{y}_{\text{new}} = \frac{1}{n + 2} \cdot \left( \Delta \tilde{y} + \sum_{i=1}^{n} \Delta y_i + \Delta m \right)$, so its variance is $\sigma^2 \left[ \tilde{Y}_{\text{new}} \right] = \frac{\varepsilon^2}{3 \cdot (n + 2)} \ll \frac{\varepsilon^2}{3} = \sigma^2 \left[ \tilde{Y} \right]$. 
17. Let Us Use $\tilde{Y}_{\text{new}}$ When Estimating $\bar{y}$

- Let us compute $\bar{Y}_{\text{new}} = \tilde{Y}_{\text{new}} + \sum_{i=1}^{n} |Y_i - \tilde{Y}_{\text{new}}|.$

- Here, when $s_i \in \{-1, 1\}$ are the signs of $y_i - \tilde{y}$, we get:
  \[
  \bar{y} = \tilde{y} + \sum_{i=1}^{n} s_i \cdot (y_i - \tilde{y}) = \left(1 - \sum_{i=1}^{n} s_i\right) \cdot \tilde{y} + \sum_{i=1}^{n} s_i \cdot y_i.
  \]

- Thus, $\Delta \bar{y}_{\text{new}} = \left(1 - \sum_{i=1}^{n} s_i\right) \cdot \Delta \tilde{y}_{\text{new}} + \sum_{i=1}^{n} s_i \cdot \Delta y_i,$ so
  \[
  \sigma^2 = \left(1 - \sum_{i=1}^{n} s_i\right)^2 \cdot \frac{\varepsilon^2}{3 \cdot (n + 2)} + \sum_{i=1}^{n} \frac{\varepsilon^2}{3}.
  \]

- Here, $|s_i| \leq 1$, so $\left|1 - \sum_{i=1}^{n} s_i\right| \leq n + 1$, and
  \[
  \sigma^2 \leq \frac{\varepsilon^2}{3} \cdot (2n + 1).
  \]
18. Using $\tilde{Y}_\text{new}$ (cont-d)

- We have $\Delta \bar{y}_\text{new} = \left(1 - \sum_{i=1}^{n} s_i\right) \cdot \Delta \tilde{y}_\text{new} + \sum_{i=1}^{n} s_i \cdot \Delta y_i$.

- Due to the Central Limit Theorem, $\Delta \bar{y}_\text{new}$ is $\approx$ normal.

- We know that $\sigma^2 \leq \frac{\varepsilon^2}{3} \cdot (2n + 1)$.

- Thus, with certainty depending on $k_0$, we have

$$\bar{y} \leq \bar{Y}_\text{new} + k_0 \cdot \sigma \leq \bar{Y}_\text{new} + k_0 \cdot \frac{\varepsilon}{\sqrt{3}} \cdot \sqrt{2n + 1} :$$

  - with certainty 95% for $k_0 = 2$,
  - with certainty 99.9% for $k_0 = 3$, etc.

- Here, inaccuracy grows as $\sqrt{2n + 1}$.

- This is much better than in the traditional approach, where it grows $\sim 2n + 1$.  

$\Delta y$ and $\bar{y}$
19. Resulting Algorithm

- **We know:** \( F(x_1, \ldots, x_n), \varepsilon, \tilde{x}_i \) and \( \Delta_i \).
- **We want:** to find the range of \( f(x_1, \ldots, x_n) \) when \( x_i \in [\tilde{x}_i - \Delta_i, \tilde{x}_i + \Delta_i] \).
- **Algorithm:**

  1) compute \( \tilde{Y} = F(\tilde{x}_1, \ldots, \tilde{x}_n) \),
      
      \[
      M = F(\tilde{x}_1 - \Delta_1, \ldots, \tilde{x}_n - \Delta_n), \quad \text{and} \]
      
      \[
      Y_i = F(\tilde{x}_1, \ldots, \tilde{x}_{i-1}, \tilde{x}_i + \Delta_i, \tilde{x}_{i+1}, \ldots, \tilde{x}_n);
      \]

  2) compute \( \tilde{Y}_{\text{new}} = \frac{1}{n + 2} \left( \tilde{Y} + \sum_{i=1}^{n} Y_i + M \right) \),

      \[
      \tilde{b} = \tilde{Y}_{\text{new}} + \sum_{i=1}^{n} \left| Y_i - \tilde{Y}_{\text{new}} \right| + k_0 \cdot \sqrt{2n + 1} \cdot \frac{\varepsilon}{\sqrt{3}}; \]

      \[
      \bar{b} = \tilde{Y}_{\text{new}} - \sum_{i=1}^{n} \left| Y_i - \tilde{Y}_{\text{new}} \right| - k_0 \cdot \sqrt{2n + 1} \cdot \frac{\varepsilon}{\sqrt{3}}.
      \]
20. A Similar Improvement Is Possible for the Cauchy Method

• In the Cauchy method, we compute $\tilde{Y}$ and the values

$$Y^{(k)} = F(\tilde{x}_1 + \eta_1^{(k)}, \ldots, \tilde{x}_n + \eta_n^{(k)}).$$

• We can then compute the improved estimate for $\tilde{y}$, as:

$$\tilde{Y}_{\text{new}} = \frac{1}{N + 1} \cdot \left( \bar{Y} + \sum_{k=1}^{N} Y^{(k)} \right).$$

• We can now use this improved estimate when estimating the differences $\Delta y^{(k)}$: namely, we compute

$$Y^{(k)} - \tilde{Y}_{\text{new}}.$$

- **Problem:** reconstruct the velocity of sound $v_i$ at different spatial locations and at different depths.
- **What we know:** the travel-times $t_j$ of a seismic signal from the set-up explosion to seismic stations.
- **Hole’s iterative algorithm:**
  - we start with geology-motivated values $v_i^{(1)}$;
  - based on the current approximation $v_i^{(k)}$, we estimate the travel times $t_j^{(k)}$;
  - update $v_i$: $\frac{1}{v_i^{(k+1)}} = \frac{1}{v_i^{(k)}} + \frac{1}{n_i} \cdot \sum_j \frac{t_j - t_j^{(k)}}{L_j}$.
- Using $\tilde{Y}_{\text{new}}$ decreased the inaccuracy $\sigma$, on average, by 15%; $\sigma$ increased only in one case (only by 7%).
22. Case Study: Seismic Inverse Problem in the Geosciences
23. Can We Further Improve the Accuracy?

- The inaccuracy $Y \neq y$ is caused by using elements of finite size $h$.

- This inaccuracy is proportional to $h$.

- If we decrease $h$ to $h'$, we thus need $K \overset{\text{def}}{=} \frac{h^3}{(h')^3}$ more cells, so we need $K$ times more computations.

- Thus, the accuracy decreases as $3\sqrt{K}$.

- New idea: select $K$ small vectors $(\Delta_1^{(k)}, \ldots, \Delta_n^{(k)})$ which add up to 0, and estimate $\tilde{y}$ as

$$Y_K(x_1, \ldots, x_n) = \frac{1}{K} \sum_{k=1}^K F \left( x_1 + \Delta_1^{(k)}, \ldots, x_n + \Delta_n^{(k)} \right).$$

- Averaging $K$ independent random errors decreases the inaccuracy by a factor of $\sqrt{K}$, much faster than $3\sqrt{K}$. 
Part III
How to Speed Up Computations – by Processing Different Types of Uncertainty Separately
24. Cases for Which a Speed-Up Is Possible

- Sometimes, all membership functions are “of the same type”: \( \mu(z) = \mu_0(k \cdot z) \) for some symmetric \( \mu_0(z) \).

- Example: for triangular functions,
  \[
  \mu_0(z) = \max(1 - |z|, 0).
  \]

- In this case, \( \mu(z) \geq \alpha \) is equivalent to \( \mu_0(k \cdot z) \geq \alpha \), so \( \alpha \Delta_0 = k \cdot \alpha \Delta \) and \( 0 \Delta_0 = k \cdot 0 \Delta \).

- Thus, \( \alpha \Delta = f(\alpha) \cdot 0 \Delta \), where \( f(\alpha) \overset{\text{def}}{=} \frac{\alpha \Delta_0}{0 \Delta_0} \).

- For example, for a triangular membership function, we have \( f(\alpha) = 1 - \alpha \).

- So, if we know the type \( \mu_0 \) (hence \( f(\alpha) \)), and we know the 0-cut, we can compute all \( \alpha \)-cuts as \( \alpha \Delta = f(\alpha) \cdot 0 \Delta \).

- So, if \( \mu_i(\Delta x_i) \) are of the same type, then for all \( \alpha \), we have \( \alpha \Delta_i = f(\alpha) \cdot 0 \Delta_i \).
25. When a Speed-Up Is Possible (cont-d)

- We know that \( \alpha \Delta = \sum_{i=1}^{n} |c_i| \cdot \alpha \Delta_i \).

- For \( \alpha \Delta_i = f(\alpha) \cdot 0 \Delta_i \), we get

\[
\alpha \Delta = \sum_{i=1}^{n} |c_i| \cdot f(\alpha) \cdot 0 \Delta_i.
\]

- So, \( \alpha \Delta = f(\alpha) \cdot \sum_{i=1}^{n} |c_i| \cdot 0 \Delta_i = f(\alpha) \cdot 0 \Delta. \)

- Thus, if all \( \mu(x) \) are of the same type \( \mu_0(z) \), there is no need to compute \( \alpha \Delta \) eleven times:
  - it is sufficient to compute \( 0 \Delta \);
  - to find all other values \( \alpha \Delta \), we simply multiply \( 0 \Delta \) by the factors \( f(\alpha) \) corresponding to \( \mu_0(z) \).
26. A More General Case

- A more general case is:
  - when we have a list of $T$ different types of uncertainty – i.e., types of membership functions, and
  - each approximation error $\Delta x_i$ consists of $\leq T$ components of the corresponding type $t$:
    \[ \Delta x_i = \sum_{t=1}^{T} \Delta x_{i,t}. \]

- For example:
  - type $t = 1$ may correspond to intervals (which are, of course, a particular case of fuzzy uncertainty),
  - type $t = 2$ may correspond to triangular membership functions, etc.
27. How This Case Is Processed Now

- **First stage:**
  - we use the known membership functions $\mu_{i,t}(\Delta x_{i,t})$
  - to find the memberships functions $\mu_{i}(\Delta x_{i})$ that correspond to the sum $\Delta x_{i}$.

- **Second stage:** we use $\mu_{i}(\Delta x_{i})$ to compute the desired membership function $\mu(\Delta y)$.

- **Problem:** on the second stage, we apply the above formula eleven times:

$$\alpha \Delta = \sum_{i=1}^{n} |c_i| \cdot \alpha \Delta_i.$$
28. Main Idea

- We have \( \Delta y = \sum_{i=1}^{n} c_i \cdot \Delta x_i \), where

\[
\Delta x_i = \sum_{t=1}^{T} \Delta x_{i,t}.
\]

- Thus, \( \Delta y = \sum_{i=1}^{n} c_i \cdot \left( \sum_{t=1}^{T} \Delta x_{i,t} \right) \).

- Grouping together all the terms corr. to type \( t \), we get

\[
\Delta y = \sum_{t=1}^{T} \Delta y_t, \quad \text{where } \Delta y_t \overset{\text{def}}{=} \sum_{i=1}^{n} c_i \cdot \Delta x_{i,t}.
\]

- For each \( t \), we are combining membership functions of the same type, so it is enough to compute \( \Delta_t^0 \).

- Then, we add the resulting membership functions – by adding the corresponding \( \alpha \)-cuts.
29. Resulting Algorithm

- Let $[-0\Delta_{i,t}, 0\Delta_{i,t}]$ be 0-cuts of the membership functions $\mu_{i,t}(\Delta x_{i,t})$.

- Based on these 0-cuts, we compute, for each type $t$, the values $0\Delta_t = \sum_{i=1}^{n} |c_i| \cdot 0\Delta_{i,t}$.

- Then, for $\alpha = 0, \alpha = 0.1, \ldots$, and for $\alpha = 1.0$, we compute the values $\alpha\Delta_t = f_t(\alpha) \cdot 0\Delta_t$.

- Finally, we add up $\alpha$-cuts corresponding to different types $t$, to come up with the expression $\alpha\Delta = \sum_{t=1}^{T} \alpha\Delta_t$.

- Comment. We can combine the last two steps into a single step: $\alpha\Delta = \sum_{t=1}^{T} f_t(\alpha) \cdot 0\Delta_t$. 

30. The New Algorithm Is Much Faster

- The original algorithm computed the above formula eleven times:

\[ \alpha \Delta = \sum_{i=1}^{n} |c_i| \cdot \alpha \Delta_i. \]

- The new algorithm uses the corresponding formula \( T \) times, i.e., as many times as there are types.

- All the other computations are much faster, since they do not grow with the input size \( n \).

- Thus, if the number \( T \) of different types is smaller than eleven, the new methods is much faster.

- Example: for \( T = 2 \) types (e.g., intervals and triangular \( \mu(x) \)), we get a \( \frac{11}{2} = 5.5 \) times speedup.
31. Conclusions and Future Work

• We can therefore conclude that sometimes, it is beneficial to process different types of uncertainty separately.

• Namely, it is beneficial when we have ten or fewer different types of uncertainty.

• The fewer types of uncertainty we have, the faster the resulting algorithm.

• We plan to test this idea of several actual data processing examples.

• We also plan to extend this idea to other types of uncertainty, in particular, to probabilistic uncertainty.
Part IV
Towards a Better Understandability of Uncertainty-Estimating Algorithms: Explaining the Need for Non-Realistic Monte-Carlo Simulations
32. Formulation of the Problem: Reminder

- **Good news:** Cauchy-based Monte-Carlo method is an efficient way of estimating interval uncertainty.

- **Limitation:** this method is *not realistic*; indeed:
  - we know that $\Delta x_i$ is *inside* $[-\Delta_i, \Delta_i]$, but
  - Cauchy-distributed variable has a high probability to be *outside* this interval.

- **Natural question:** is it a limitation of our method, or of a problem itself?

- **Our answer:** for interval uncertainty, a realistic Monte-Carlo method is not possible.
33. **Proof: Case of Independent Variables**

- It is sufficient to prove that we cannot get the correct estimate for *one* specific function

\[ f(x_1, \ldots, x_n) = x_1 + \ldots + x_n, \quad \text{when} \quad \Delta y = \Delta x_1 + \ldots + \Delta x_n. \]

- When each variables \(\Delta x_i\) is in the interval \([-\delta, \delta]\), then the range of \(\Delta y\) is \([-\Delta, \Delta]\), where \(\Delta = n \cdot \delta\).

- In Monte-Carlo, \(\Delta y^{(k)} = \Delta x_1^{(k)} + \ldots + \Delta x_n^{(k)}\).

- \(\Delta_i^{(k)}\) are i.i.d. Due to the Central Limit Theorem, when \(n \to \infty\), the distribution of the sum tends to Gaussian.

- For a normal distribution, with very high confidence, \(\Delta y \in [\mu - k \cdot \sigma, \mu + k \cdot \sigma]\).

- Here, \(\sigma \sim \sqrt{n}\), so this interval has width \(w \sim \sqrt{n}\).

- However, the actual range of \(\Delta y\) is \(\sim n \gg w\). Q.E.D.
34. General Case

- Let’s take \( f(x_1, \ldots, x_n) = s_1 \cdot x_1 + \ldots + s_n \cdot x_n \), where \( s_i \in \{-1, 1\} \).

- Then, \( \Delta = \sum_{i=1}^{n} |c_i| \cdot \Delta_i = n \cdot \delta \).

- Let \( \varepsilon > 0, \delta > 0 \), and \( p \in (0, 1) \). We consider probability distributions \( P \) on the set of all vectors \((\Delta x_1, \ldots, \Delta x_n) \in [-\delta, \delta] \times \ldots \times [-\delta, \delta]\).

- We say that \( P \) is a \((p, \varepsilon)\)-realistic Monte-Carlo estimation (MCE) if for all \( s_i \in \{-1, 1\} \), we have
  \[
  \text{Prob}(s_1 \cdot \Delta x_1 + \ldots + s_n \cdot \Delta x_n \geq n \cdot \delta \cdot (1 - \varepsilon)) \geq p.
  \]

- **Result.** If for every \( n \), we have a \((p_n, \varepsilon)\)-realistic MCE, then \( p_n \leq \beta \cdot n \cdot c^n \) for some \( \beta > 0 \) and \( c < 1 \).

- For probability \( p_n \), we need \( 1/p_n \sim c^{-n} \) simulations – more than \( n + 1 \) for numerical differentiation.
35. Why Cauchy Distribution: Formulation of the Problem

• We want to find a family of probability distributions with the following property:
  
  – when independent $X_1, \ldots, X_n$ have distributions from this family with parameters $\Delta_1, \ldots, \Delta_n$,
  
  – then each $Y = c_1 \cdot X_1 + \ldots + c_n \cdot X_n \sim \Delta \cdot X$, where $X$ corr. to parameter 1, and $\Delta = \sum_{i=1}^{n} |c_i| \cdot \Delta_i$.

• In particular, for $\Delta_1 = \ldots = \Delta_n = 1$, the desired property of this probability distribution is as follows:
  
  – if we have $n$ independent identically distributed random variables $X_1, \ldots, X_n$,
  
  – then each $Y = c_1 \cdot X_1 + \ldots + c_n \cdot X_n$ has the same distribution as $\Delta \cdot X_i$, where $\Delta = \sum_{i=1}^{n} |c_i|$.
36. Analysis of the Problem

- For $n = 1$ and $c_1 = -1$, the desired property says that $-X \sim X$, the distribution is even.

- A usual way to describe a probability distribution is to use a probability density function $\rho(x)$.

- Often, it is convenient to use its Fourier transform – the characteristic function $\chi_X(\omega) \overset{\text{def}}{=} E[\exp(i \cdot \omega \cdot X)]$.

- When $X_i$ are independent, then for $S = X_1 + X_2$:
  \[
  \chi_S(\omega) = E[\exp(i \cdot \omega \cdot S)] = E[\exp(i \cdot \omega \cdot (X_1 + X_2))] = \\
  E[\exp(i \cdot \omega \cdot X_1 + i \cdot \omega \cdot X_2)] = \\
  E[\exp(i \cdot \omega \cdot X_1) \cdot \exp(i \cdot \omega \cdot X_2)].
  \]

- Since $X_1$ and $X_2$ are independent,
  \[
  \chi_S(\omega) = E[\exp(i \cdot \omega \cdot X_1)] \cdot E[\exp(i \cdot \omega \cdot X_2)] = \chi_{X_1}(\omega) \cdot \chi_{X_2}(\omega).
  \]
37. Analysis of the Problem (cont-d)

- Similarly, for \( Y = \sum_{i=1}^{n} c_i \cdot X_i \), we have

\[
\chi_Y(\omega) = E[\exp(i \cdot \omega \cdot Y)] = E \left[ \exp \left( i \cdot \omega \cdot \sum_{i=1}^{n} c_i \cdot X_i \right) \right] = \\
E \left[ \prod_{i=1}^{n} \exp \left( i \cdot \omega \cdot c_i \cdot X_i \right) \right] = \prod_{i=1}^{n} \chi_X(\omega \cdot c_i).
\]

- The desired property is \( Y \sim \Delta \cdot X \), so

\[
\prod_{i=1}^{n} \chi_X(\omega \cdot c_i) = \chi_{\Delta \cdot X}(\omega) = E[\exp(i \cdot \omega \cdot (\Delta \cdot X))] \chi_X(\omega \cdot \Delta),
\]

so \( \chi_X(c_1 \cdot \omega) \cdot \ldots \cdot \chi_X(c_n \cdot \omega) = \chi_X((|c_1| + \ldots + |c_n|) \cdot \omega) \).

- In particular, for \( n = 1, c_1 = -1 \), we get \( \chi_X(-\omega) = \chi_X(\omega) \), so \( \chi_X(\omega) \) should be an even function.
38. Analysis of the Problem (cont-d)

- Reminder:

\[ \chi_X(c_1 \cdot \omega) \cdot \ldots \cdot \chi_X(c_n \cdot \omega) = \chi_X((|c_1| + \ldots + |c_n|) \cdot \omega). \]

- For \( n = 2, c_1 > 0, c_2 > 0, \) and \( \omega = 1, \) we get

\[ \chi_X(c_1 + c_2) = \chi_X(c_1) \cdot \chi_X(c_2). \]

- The characteristic function should be measurable.

- *Known:* the only measurable functions with this property are \( \chi_X(\omega) = \exp(-k \cdot \omega) \) for some \( k. \)

- Due to evenness, for a general \( \omega, \) we get \( \chi_X(\omega) = \exp(-k \cdot |\omega|). \)

- By applying the inverse Fourier transform, we conclude that \( X \) is Cauchy distributed.

- *Conclusion:* so, only Cauchy distribution works.
Part V

How General Can We Go: What Is Computable and What Is Not
39. Need to Take Uncertainty Into Account When Processing Data: Reminder

• In practice, we are often interested in a quantity $y$ which is difficult to measure directly.

• *Examples*: distance to a star, amount of oil in the well, tomorrow’s weather.

• *Solution*: find easier-to-measure quantities $x_1, \ldots, x_n$ related to $y$ by a known dependence $y = f(x_1, \ldots, x_n)$.

• Then, we measure $x_i$ and use measurement results $\tilde{x}_i$ to compute an estimate $\tilde{y} = f(\tilde{x}_1, \ldots, \tilde{x}_n)$.

• Measurements are never absolutely accurate, so even if the model $f$ is exact, $\tilde{x}_i \neq x_i$ leads to $\Delta y \overset{\text{def}}{=} \tilde{y} - y \neq 0$.

• It is important to use information about measurement errors $\Delta x_i \overset{\text{def}}{=} \tilde{x}_i - x_i$ to estimate the accuracy $\Delta y$. 

40. **We Often Have Imprecise Probabilities**

- *Usual assumption:* we know the probabilities for $\Delta x_i$.
- To find them, we measure the same quantities:
  - with our measuring instrument (MI) and
  - with a much more accurate MI, with $\tilde{x}_i^{st} \approx x_i$.
- In two important cases, this does not work:
  - state-of-the-art measurements, and
  - measurements on the shop floor.
- Then, we have partial information about probabilities.
- Often, all we know is an upper bound $|\Delta x_i| \leq \Delta_i$.
- Then, we only know that $x_i \in [\tilde{x}_i - \Delta_i, \tilde{x}_i + \Delta_i]$ and
  \[
  y \in [y, \bar{y}] \overset{\text{def}}{=} \{ f(x_1, \ldots, x_n) : x_i \in [\tilde{x}_i - \Delta_i, \tilde{x}_i + \Delta_i] \}.
  \]
- Computing $[y, \bar{y}]$ is known as *interval computation.*
41. How Do We Describe Imprecise Probabilities?

- **Ultimate goal of most estimates:** to make decisions.
- **Known:** a rational decision-maker maximizes expected utility $E[u(y)]$.
- For smooth $u(y)$, $y \approx \tilde{y}$ implies that
  \[ u(y) = u(\tilde{x}) + (y - \tilde{y}) \cdot u'(\tilde{y}) + \frac{1}{2} \cdot (y - \tilde{y})^2 \cdot u''(\tilde{y}). \]
- So, to find $E[u(y)]$, we must know moments $E[(y - \tilde{y})^k]$.
- Often, $u(x)$ abruptly changes: e.g., when pollution level exceeds $y_0$; then $E[u(y)] \sim F(y) \overset{\text{def}}{=} \text{Prob}(y \leq y_0)$.
- From $F(y)$, we can estimate moments, so $F(x)$ is enough.
- Imprecise probabilities mean that we know $F(y)$, we only know bounds ($p$-box) $\underline{F}(y) \leq F(y) \leq \overline{F}(y)$. 
42. What Is Computable?

- Computations with p-boxes are practically important.
- It is thus desirable to come up with efficient algorithms which are as general as possible.
- It is known that too general problems are often not computable.
- To avoid wasting time, it is therefore important to find out what can be computed.
- At first glance, this question sounds straightforward:
  - to describe a cdf, we can consider a computable function $F(x)$;
  - to describe a p-box, we consider a computable function interval $[\underline{F}(x), \overline{F}(x)]$.
- Often, we can do that, but we will show that sometimes, we need to go beyond function intervals.
43. Reminder: What Is Computable?

• A real number $x$ corresponds to a value of a physical quantity.
• We can measure $x$ with higher and higher accuracy.
• So, $x$ is called *computable* if there is an algorithm, that, given $k$, produces a rational $r_k$ s.t. $|x - r_k| \leq 2^{-k}$.
• A *computable function* computes $f(x)$ from $x$.
• We can only use approximations to $x$.
• So, an algorithm for computing a function can, given $k$, request a $2^{-k}$-approximation to $x$.
• Most usual functions are thus computable.
• *Exception:* step-function $f(x) = 0$ for $x < 0$ and $f(x) = 1$ for $x \geq 0$.
• Indeed, no matter how accurately we know $x \approx 0$, from $r_k = 0$, we cannot tell whether $x < 0$ or $x \geq 0$. 
44. Consequences for Representing a cdf $F(x)$

- We would like to represent a general probability distribution by its cdf $F(x)$.
- From the purely mathematical viewpoint, this is indeed the most general representation.
- At first glance, it makes sense to consider computable functions $F(x)$.
- For many distributions, e.g., for Gaussian, $F(x)$ is computable.
- However, when $x = 0$ with probability 1, the cdf $F(x)$ is exactly the step-function.
- And we already know that the step-function is not computable.
- Thus, we need to find an alternative way to represent cdf’s – beyond computable functions.
45. Back to the Drawing Board

- Each value $F(x)$ is the probability that $X \leq x$.
- We cannot empirically find exact probabilities $p$.
- We can only estimate frequencies $f$ based on a sample of size $N$.
- For large $N$, the difference $d \overset{\text{def}}{=} p - f$ is asymptotically normal, with $\mu = 0$ and $\sigma = \sqrt{\frac{p \cdot (1 - p)}{N}}$.
- Situations when $|d - \mu| < 6\sigma$ are negligibly rare, so we conclude that $|f - p| \leq 6\sigma$.
- For large $N$, we can get $6\sigma \leq \delta$ for any accuracy $\delta > 0$.
- We get a sample $X_1, \ldots, X_N$.
- We don’t know the exact values $X_i$, only measured values $\tilde{X}_i$ s.t. $|\tilde{X}_i - X_i| \leq \varepsilon$ for some accuracy $\varepsilon$.
- So, what we have is a frequency $f = \text{Freq}(\tilde{X}_i \leq x)$. 

46. Resulting Definition

- Here, \( X_i \leq x - \varepsilon \Rightarrow \tilde{X}_i \leq x \Rightarrow X_i \leq x + \varepsilon \), so
  \[
  \text{Freq}(X_i \leq x - \varepsilon) \leq f = \text{Freq}(\tilde{X}_i \leq x) \leq \text{Freq}(X_i \leq x + \varepsilon).
  \]

- Frequencies are \( \delta \)-close to probabilities, so we arrive at the following:

- *For every* \( x, \varepsilon > 0, \text{ and } \delta > 0, \) *we get a rational number* \( f \) *such that* \( F(x - \varepsilon) - \delta \leq f \leq F(x + \varepsilon) + \delta. \)

- This is how we define a computable cdf \( F(x) \).

- In the computer, to describe a distribution on an interval \([T, \overline{T}]\):
  - we select a grid \( x_1 = T, x_2 = T + \varepsilon, \ldots, \) and
  - we store the corr. frequencies \( f_i \) with accuracy \( \delta \).

- A class of possible distribution is represented, for each \( \varepsilon \) and \( \delta \), by a finite list of such approximations.
47. **First Equivalent Definition**

• *Original:* \(\forall x \forall \varepsilon > 0 \forall \delta > 0\), we get a rational \(f\) such that
\[
F(x - \varepsilon) - \delta \leq f \leq F(x + \varepsilon) + \delta.
\]

• *Equivalent:* \(\forall x \forall \varepsilon > 0 \forall \delta > 0\), we get a rational \(f\) which is \(\delta\)-close to \(F(x')\) for some \(x'\) such that \(|x' - x| \leq \varepsilon\).

• *Proof of equivalence:*
  
  - We know that \(F(x + \varepsilon) - F(x + \varepsilon/3) \to 0\) as \(\varepsilon \to 0\).
  
  - So, for \(\varepsilon = 2^{-k}\), \(k = 1, 2, \ldots\), we take \(f\) and \(f'\) s.t.
    \[
    F(x + \varepsilon/3) - \delta/4 \leq f \leq F(x + (2/3) \cdot \varepsilon) + \delta/4
    \]
    \[
    F(x + (2/3) \cdot \varepsilon) - \delta/4 \leq f' \leq F(x + \varepsilon) + \delta/4.
    \]

  - We stop when \(f\) and \(f'\) are sufficiently close:
    \[
    |f - f'| \leq \delta.
    \]

  - Thus, we get the desired \(f\).
48. Second Equivalent Definition

- We start with pairs \((x_1, f_1), (x_2, f_2), \ldots\)
- When \(f_{i+1} - f_i > \delta\), we add intermediate pairs
  \((x_i, f_i + \delta), (x_i, f_i + 2\delta), \ldots, (x_i, f_{i+1})\).
- The resulting set of pairs is \((\varepsilon, \delta)\)-close to the graph
  \(\{(x, y) : F(x-0) \leq y \leq F(x)\}\) in Hausdorff metric \(d_H\).
- \((x, y)\) and \((x', y')\) are \((\varepsilon, \delta)\)-close if \(|x - x'| \leq \varepsilon\) and \(|y - y'| \leq \delta\).
- The sets \(S\) and \(S'\) are \((\varepsilon, \delta)\)-close if:
  - for every \(s \in S\), there is a \((\varepsilon, \delta)\)-close point \(s' \in S'\);
  - for every \(s' \in S'\), there is a \((\varepsilon, \delta)\)-close point \(s \in S\).
- Compacts with metric \(d_H\) form a computable compact.
- So, \(F(x)\) is a monotonic computable object in this compact.
49. What Can Be Computed: A Positive Result for the 1D Case

- **Reminder:** we are interested in $F(x)$ and $E_{F(x)}[u(x)]$ for smooth $u(x)$.

- **Reminder:** estimate for $F(x)$ is part of the definition.

- **Question:** computing $E_{F(x)}[u(x)]$ for smooth $u(x)$.

- **Our result:** there is an algorithm that:
  - given a computable cdf $F(x)$,
  - given a computable function $u(x)$, and
  - given accuracy $\delta > 0$,
  - computes $E_{F(x)}[u(x)]$ with accuracy $\delta$.

- For computable classes $\mathcal{F}$ of cdfs, a similar algorithm computes the range of possible values

$$[u, \bar{u}] \overset{\text{def}}{=} \{ E_{F(x)}[u(x)] : F(x) \in \mathcal{F} \}.$$
50. **Proof: Main Idea**

- Computable functions are computably continuous: for every $\delta > 0$, we can compute $\varepsilon > 0$ s.t.
  \[ |x - x'| \leq \varepsilon \Rightarrow |f(x) - f(x')| \leq \delta. \]

- We select $\varepsilon$ corr. to $\delta/4$, and take a grid with step $\varepsilon/4$.

- For each $x_i$, the value $f_i$ is $(\delta/4)$-close to $F(x'_i)$ for some $x'_i$ which is $(\varepsilon/4)$-close to $x_i$.

- The function $u(x)$ is $(\delta/2)$-close to a piece-wise constant function $u'(x) = u(x_i)$ for $x \in [x'_i, x'_{i+1}]$.

- Thus, $|E[u(x)] - E[u'(x)]| \leq \delta/2$.

- Here, $E[u'(x)] = \sum_i u(x_i) \cdot (F(x'_{i+1}) - F(x'_i))$.

- Here, $F(x'_i)$ is close to $f_i$ and $F(x'_{i+1})$ is close to $f_{i+1}$.

- Thus, $E[u'(x)]$ (and hence, $E[u(x)]$) is computably close to a computable sum $\sum_i u(x_i) \cdot (f_{i+1} - f_i)$. 
51. What to Do in a Multi-D Case?

• For each $g(x)$, $y$, $\varepsilon > 0$, and $\delta > 0$, we can find a frequency $f$ such that:

$$|P(g(x) \leq y') - f| \leq \varepsilon$$

for some $y'$ s.t. $|y - y'| \leq \delta$.

• We select an $\varepsilon$-net $x_1, \ldots, x_n$ for $X$. Then,

$$X = \bigcup_{i} B_{\varepsilon}(x_i), \quad \text{where} \quad B_{\varepsilon}(x) \overset{\text{def}}{=} \{x' : d(x, x') \leq \varepsilon\}.$$

• We select $f_1$ which is close to $P(B_{\varepsilon'}(x_1))$ for all $\varepsilon'$ from some interval $[\varepsilon, \bar{\varepsilon}]$ which is close to $\varepsilon$.

• We then select $f_2$ which is close to $P(B_{\varepsilon'}(x_1) \cup B_{\varepsilon'}(x_2))$ for all $\varepsilon'$ from some subinterval of $[\varepsilon, \bar{\varepsilon}]$, etc.

• Then, we get approximations to probabilities of the sets $B_{\varepsilon}(x_i) - (B_{\varepsilon}(x_1) \cup \ldots \cup B_{\varepsilon}(x_{i-1}))$.

• This lets us compute the desired values $E[u(x)]$. 
Part VI

Conclusions and Future Work
52. Conclusions

• In many practical applications, we process measurement results and expert estimates.

• Measurements and expert estimates are never absolutely accurate.

• Their results are slightly different from the actual (unknown) values of the corresponding quantities.

• It is therefore desirable to analyze how measurement inaccuracy affects the results of data processing.

• There exist numerous methods for estimating the accuracy of the results of data processing.

• These methods cover different models of inaccuracy: probabilistic, interval, and fuzzy.
53. Conclusions (cont-d)

- To be useful in engineering applications, the uncertainty methods should satisfy the following objectives.
- They should provide accurate estimate for the resulting uncertainty.
- They should not take too much computation time.
- They should be understandable to engineers.
- They should be sufficiently general to cover all kinds of uncertainty.
54. Conclusions (final)

- In this thesis, on several case studies, we show how we can achieve these four objectives.

- We show that we can get more accurate estimates by properly taking model inaccuracy into account.

- We show that we can speed up computations by processing different types of uncertainty differently.

- We show that we can make uncertainty-estimating algorithms more understandable.

- We also analyze how general uncertainty-estimating algorithms can be.
55. Future Work

- In our future work, we plan to continue working in these four directions.

- In particular, we plan to extend our speed-up algorithms from fuzzy to probabilistic uncertainty.

- One of the main reasons for estimation and data processing is to make decisions; we thus plan to analyze:
  - how the corresponding uncertainty affects decision making, and
  - what is the best way to make decisions under different types of uncertainty.

- We plan to apply these algorithms to practical engineering problems, e.g., pavement compaction.
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Part VII
Proofs
57. Proof of the Main Result from Part 4

- Let us pick some $\alpha \in (0, 1)$.
- Let us denote, by $m$, the number of indices $i$ or which $s_i \cdot \Delta x_i > \alpha \cdot \delta$.
- If we have $s_1 \cdot \Delta x_1 + \ldots + s_n \cdot \Delta x_n \geq n \cdot \delta \cdot (1 - \varepsilon)$, then:
  - for $n - m$ indices, we have $s_i \cdot \Delta x_i \leq \alpha \cdot \delta$ and
  - for the other $m$ indices, we have $s_i \cdot \Delta x_i \leq \delta$.
- Thus, $n \cdot \delta \cdot (1 - \varepsilon) \leq \sum_{i=1}^{n} s_i \cdot \Delta x_i \leq m \cdot \delta + (n - m) \cdot \alpha \cdot \delta$.
- Dividing this inequality by $\delta$, we get
  $$n \cdot (1 - \varepsilon) \leq m + (n - m) \cdot \alpha.$$
- So, $n \cdot (1 - \alpha - \varepsilon) \leq m \cdot (1 - \alpha)$ and $m \geq n \cdot \frac{1 - \alpha - \varepsilon}{1 - \alpha}$.
- So, we have at least $n \cdot \frac{1 - \alpha - \varepsilon}{1 - \alpha}$ indices for which $\Delta x_i$ has the same sign as $s_i$ (and for which $|\Delta x_i| > \alpha \cdot \delta$).
58. Proof from Part 4 (cont-d)

- So, for $\Delta x_i$ corr. to $(s_1, \ldots, s_n)$, at most $n \cdot \frac{\varepsilon}{1 - \alpha - \varepsilon}$ indices have a different sign than $s_i$.

- It is possible that the same tuple $\Delta x$ can serve two tuples $s \neq s'$. In this case:
  - going from $s_i$ to $\text{sign}(\Delta x_i)$ changes at most $n \cdot \frac{\varepsilon}{1 - \alpha - \varepsilon}$ signs, and
  - going from $\text{sign}(\Delta x_i)$ to $s'_i$ also changes at most $n \cdot \frac{\varepsilon}{1 - \alpha - \varepsilon}$ signs.

- Thus, between the tuples $s$ and $s'$, at most $2 \cdot \frac{\varepsilon}{1 - \alpha - \varepsilon}$ signs are different.

- In other words, for the Hamming distance $d(s, s') \overset{\text{def}}{=} \#\{i : s_i \neq s'_i\}$, we have $d(s, s') \leq 2 \cdot n \cdot \frac{\varepsilon}{1 - \alpha - \varepsilon}$. 
59. Proof from Part 4 (cont-d)

• Thus, if \( d(s,s') > 2 \cdot n \cdot \frac{\varepsilon}{1 - \alpha - \varepsilon} \), then no tuples \((\Delta x_1, \ldots, \Delta x_n)\) can serve both sign tuples \(s\) and \(s'\).

• In this case, the two sets of tuples \(\Delta x\) do not intersect:
  
  – tuples s.t. \( s_1 \cdot \Delta x_1 + \ldots + s_n \cdot \Delta x_n \geq n \cdot \delta \cdot (1 - \varepsilon) \);
  
  – tuples s.t. \( s'_1 \cdot \Delta x_1 + \ldots + s'_n \cdot \Delta x_n \geq n \cdot \delta \cdot (1 - \varepsilon) \).

• Let's take \(M\) sign tuples \(s^{(1)}, \ldots, s^{(M)}\) for which \(d(s^{(i)}, s^{(j)}) > 2 \cdot \frac{\varepsilon}{1 - \alpha - \varepsilon}\) for all \(i \neq j\).

• Then the probability \(P\) that \(\Delta x\) serves one of these sign tuples is \(\geq M \cdot p\).

• Since \(P \leq 1\), we have \(p \leq \frac{1}{M}\); so:
  
  – to prove that \(p_n\) is exponentially decreasing,
  
  – it is sufficient to find the sign tuples whose number \(M\) is exponentially increasing.
60. Proof from Part 4 (cont-d)

- Let us denote \( \beta \overset{\text{def}}{=} \frac{\varepsilon}{1 - \alpha - \varepsilon} \).

- Then, for each sign tuple \( s \), the number \( t \) of all sign tuples \( s' \) for which \( d(s, s') \leq \beta \cdot n \) is equal to the sum of:
  
  - the number of tuples \( \binom{n}{0} \) that differ from \( s \) in 0 places,
  
  - the number of tuples \( \binom{n}{1} \) that differ from \( s \) in 1 place, \ldots,
  
  - the number of tuples \( \binom{n}{\beta \cdot n} \) that differ from \( s \) in \( \beta \cdot n \) places,

- Thus, \( t = \binom{n}{0} + \binom{n}{1} + \ldots + \binom{n}{n \cdot \beta} \).
61. Proof from Part 4 (cont-d)

- When $\beta < 0.5$ and $\beta \cdot n < \frac{n}{2}$, the number of combinations $\binom{n}{k}$ increases with $k$, so $t \leq \beta \cdot n \cdot \binom{n}{\beta \cdot n}$.

- Here, $\binom{a}{b} = \frac{a!}{b! \cdot (a-b)!}$. Since $n! \sim \left(\frac{n}{e}\right)^n$, we have
  
  $$t \leq \beta \cdot n \cdot \left(\frac{1}{\beta^\beta \cdot (1-\beta)^{1-\beta}}\right)^n.$$

- Here, $\gamma \overset{\text{def}}{=} \frac{1}{\beta^\beta \cdot (1-\beta)^{1-\beta}} = \exp(S)$, where $S \overset{\text{def}}{=} -\beta \cdot \ln(\beta) - (1-\beta) \cdot \ln(1-\beta)$ is Shannon’s entropy.

- It is known that $S$ attains its largest value when $\beta = 0.5$, in which case $S = \ln(2)$ and $\gamma = \exp(S) = 2$.

- When $\beta < 0.5$, we have $S < \ln(2)$, thus, $\gamma < 2$, and $t \leq \beta \cdot n \cdot \gamma^n$ for some $\gamma < 2$. 
62. Proof from Part 4 (cont-d)

- Let us now construct the desired collection of sign tuples \( s^{(1)}, \ldots, s^{(M)} \).
  - We start with some sign tuple \( s^{(1)} \), e.g., \( s^{(1)} = (1, \ldots, 1) \).
  - Then, we dismiss \( t \leq \gamma^n \) tuples which are \( \leq \beta \)-close to \( s \), and select one of the remaining tuples as \( s^{(2)} \).
  - We then dismiss \( t \leq \gamma^n \) tuples which are \( \leq \beta \)-close to \( s^{(2)} \).
  - Among the remaining tuples, we select the tuple \( s^{(3)} \), etc.

- Once we have selected \( M \) tuples, we have thus dismissed \( t \cdot M \leq \beta \cdot n \cdot \gamma^n \cdot M \) sign tuples.

- So, as long as this number is smaller than the overall number \( 2^n \) of sign tuples, we can continue selecting.
63. Proof from Part 4 (conclusions)

- Our procedure ends when we have selected \( M \) tuples for which \( \beta \cdot n \cdot \gamma^n \cdot M \geq 2^n \).

- Thus, we have selected \( M \geq \left( \frac{2}{\gamma} \right)^n \cdot \frac{1}{\beta \cdot n} \) tuples.

- So, we have indeed selected exponentially many tuples.

- Hence, \( p_n \leq \frac{1}{M} \leq \beta \cdot n \cdot \left( \frac{\gamma}{2} \right)^n \), i.e.,

\[
p_n \leq \beta \cdot n \cdot c^n, \text{ where } c \overset{\text{def}}{=} \frac{\gamma}{2} < 1.
\]

- So, the probability \( p_n \) is indeed exponentially decreasing. The main result is proven.