

SPARSE ALGORITHMS FOR MARKOVIAN GAUSSIAN PROCESSES

WILLIAM WILKINSON^{1,2}

ARNO SOLIN¹

VINCENT ADAM^{1,3}



¹AALTO UNIVERSITY, ²THE ALAN TURING INSTITUTE, ³SECONDMIND.AI



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- GPs for time series can be reformulated as state-space models (**Markov GPs**) with efficient inference via **filtering and smoothing**.
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- Many operations during inference can be parallelised, but **GPUs do not handle sequential filtering efficiently**. **How can we speed things up?**

Markovian Gaussian Processes on 1D inputs, x ,

$$f \sim GP(\mathbf{0}, \kappa(x, x')) \iff \begin{cases} \frac{ds(x)}{dx} = \mathbf{F}s(x) + \mathbf{L}w(x) \\ f(x) = \mathbf{H}s(x) \end{cases}$$

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Compute: $\mathcal{O}((N_* + M)d^3)$

Memory: $\mathcal{O}(Md^2)$

Our main contribution is to develop **site-based inference** for sparse Markov GPs.

Approximate the GP posterior as:

$$p(\mathbf{f} | \mathbf{y}) \propto p(\mathbf{f}) \prod_n p(y_n | f_n) \approx \int p(\mathbf{u}) p(\mathbf{f} | \mathbf{u}) \prod_m t_m(\mathbf{u}_m, \mathbf{u}_{m+1}) d\mathbf{u}$$

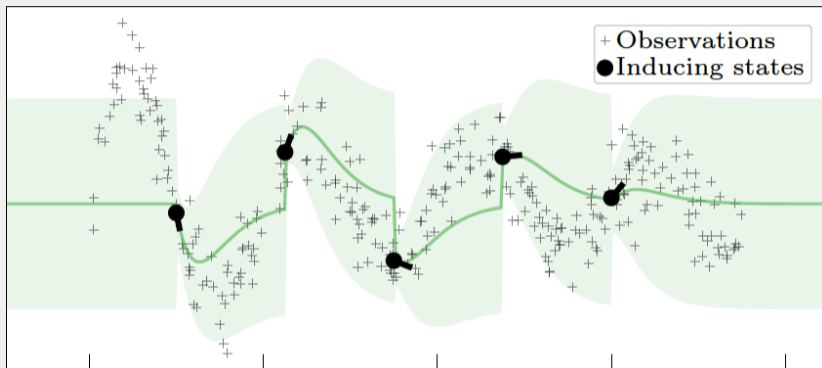
where the approximate likelihoods (sites), $t_m(\mathbf{u}_m, \mathbf{u}_{m+1})$, only depend on the **local inducing states** due to the Markov property.

All inference methods amount to different ways of updating $t_m(\cdot, \cdot)$.

- Natural gradient variational inference (VI)
- Power expectation propagation (PEP)
- Classical Kalman Smoothers

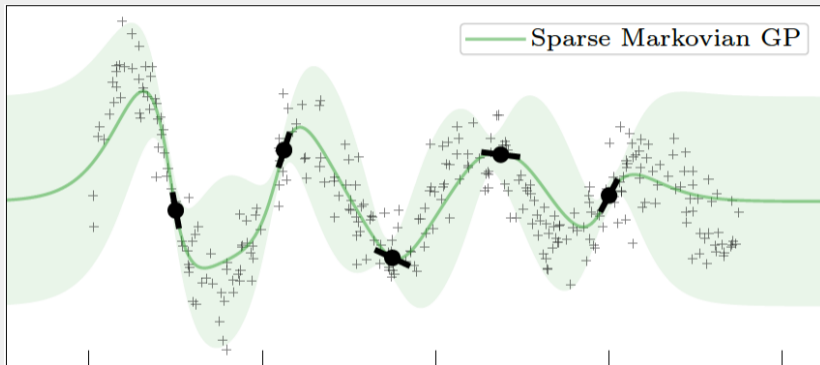
Site-based inference unifies these methods, but also has computational and stability benefits over the previous VI approach.

EXAMPLE: REGRESSION



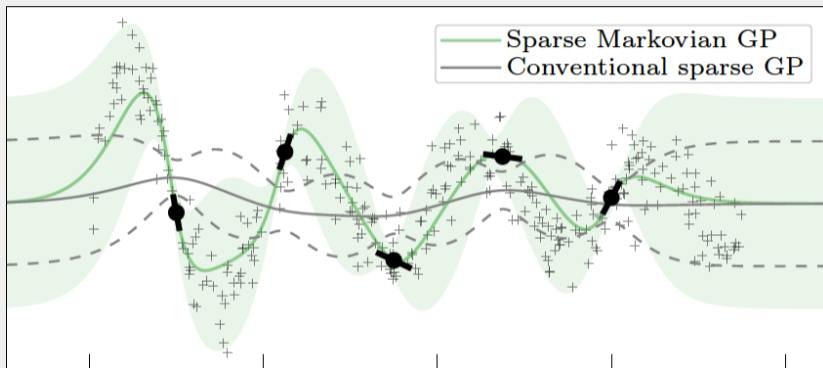
→ Forward FILTERING pass

EXAMPLE: REGRESSION



← Backward SMOOTHING pass

EXAMPLE: REGRESSION



← Backward SMOOTHING pass

THANKS FOR LISTENING

WILLIAM.WILKINSON@AALTO.FI

<https://github.com/AaltoML/Newt>