



Bayesian Neural Network and its application in ATLAS

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Neural Network following Bayesian statistical interpretation

Features:

- Fitting of probability function
- Regulator to avoid overtraining
- Uncertainty estimation
- Based on the MLP algorithm
 - Configurable as options of the algorithm
 - Available in rel. 4.1.0 (ROOT 5.28)





Generic multivariate function approximator (Think of polynomial in 1D)

Training:

- Unbinned fitting with $D = \{x_i, t_i\}$
- Cost function $(y(x,w)-t)^2 = -\log(L)$, L=P(D|w)
- Min cost function=Max likelihood
- Prediction:
 - Obtained fitted value in the phase space
 - Classification: cut at the fitted value for discrimination



Bayesian implementation (I)

Fitting probability function

- Probability $y \in [0,1]$ is more useful than proposition $y \in \{0,1\}$
- Not for probability density function $\int y d\mathbf{x} = 1 \implies PDERS$
- To constrain y between 0 and 1, transform y by $f^{(2)}(x) = 1/(1 + \exp(-x))$
- To make y=P(t==1). Bernoulli likelihood \Leftrightarrow Cross entropy cost function $-\log(L) = \sum_{i} (-t_i * \log y(x_i) - (1-t_i) * \log(1-y(x_i)))$

MLP option: EstimatorType=CE

Bayesian implementation (II)

Regulator to avoid overtraining

- Overtraining is caused by excessive complexity of NN
- A prior knowledge prefer "simpler" model ⇔ small w
 - Gaussian prior $-\log(P(\mathbf{w})) = \sum (\alpha_m \times w_m^2)$
 - P(w|D)=P(D|w)P(w). Add to the log likelihood (cost function)
- Optimize α during training
 ⇔ Adaptive complexity control
- MLP option: UseRegulator





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Bayesian implementation (III)

Uncertainty estimation

- Training:
 - Most probable value $w_{\rm MP}$
 - P(w|D)Probability of other w
- Prediction
 - Probability $P(y | \mathbf{x'}) = \int P(y | \mathbf{x'}, \mathbf{w}) * P(\mathbf{w} | \mathbf{D}) d\mathbf{w}$
 - Uncertainty of y
 - Avoid excessive extrapolation (non-trivial for multivariate analysis)
- MLP option: CalculateErrors (interface need to be completed)



Application in ATLAS analysis(I)

- Isolated di-lepton search (Exotic/SUSY)
 - Double-fake bkg: bb/cc
 - True-fake bkg: W/Z+jet
- Data-driven estimation
 - Extrapolate from nonisolated control samples to signal region
 - Weight each event by the (product of) pass/fail ratio k of the failed muon(s)



$$c = \frac{P(pass)}{1 - P(pass)}$$

Application in ATLAS analysis(II)

• P(pass) is obtained from a single-muon control sample

• Strong dependence of P(pass) over kinematics **x**



- Different distributions between control samples
- Correlation between the two leptons
- Proper parameterization of P(pass|**x**) is crucial

Application in ATLAS analysis(III)

- The BNN is used for unbinned fitting of P(pass|x)
- Training sample:
 - Single muons in background control region,
 - **D**={ x_i, t_i }
 - $\mathbf{x} = \{ p_T , H_{\phi} \}$
 - t=1 (pass isolation cut) t=0 (fail isolation cut)
 - Could add more variables for parameterization: Eta, n_vertex



2D fake rate fitted by BNN

Data-driven background estimation(V)

- Number of observed events= 149
- Number of predicted background yield= 141 ± 15





Summary

- The Bayesian implementations
 - As easy as polynomial fitting !!
 - Fitting of probability function
 - Regulator to avoid overtraining
 - Uncertainty estimation
- Probability fitting in data analysis
 - Shows good performance in one ATLAS application
 - Open the door to more delicate study
 - Could be applied to many other analysis: Trigger/Charge/ParticleID