

Learning vector fields of Differential equations on manifolds with Geometrically constrained operator-valued kernels

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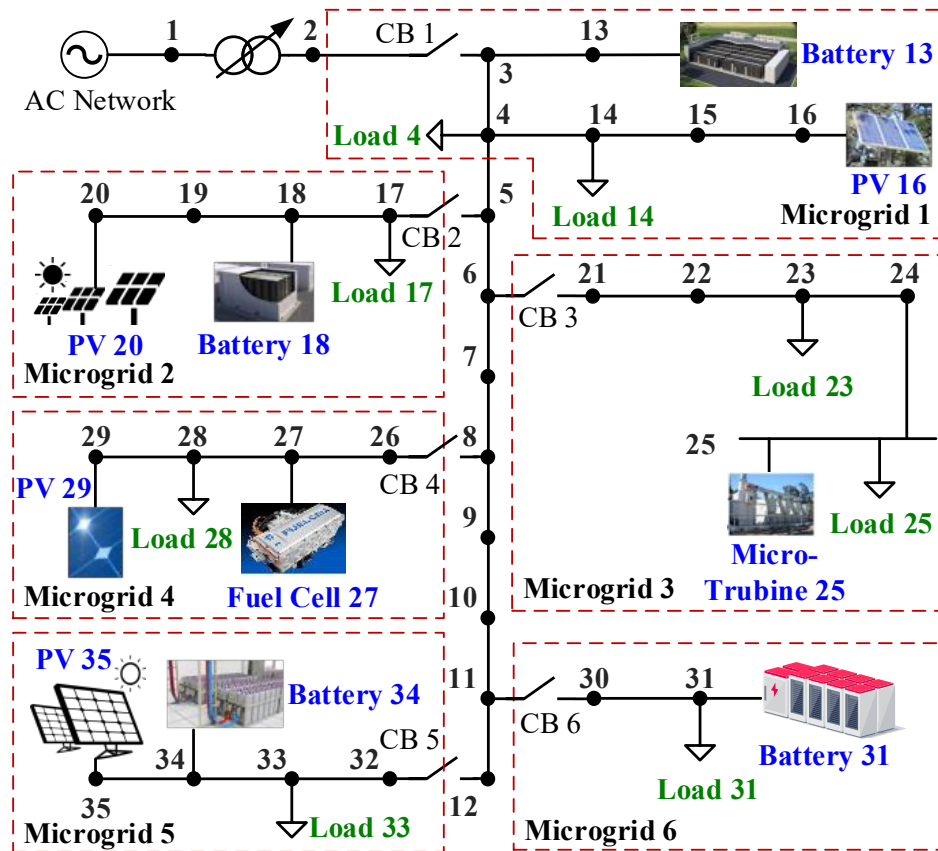
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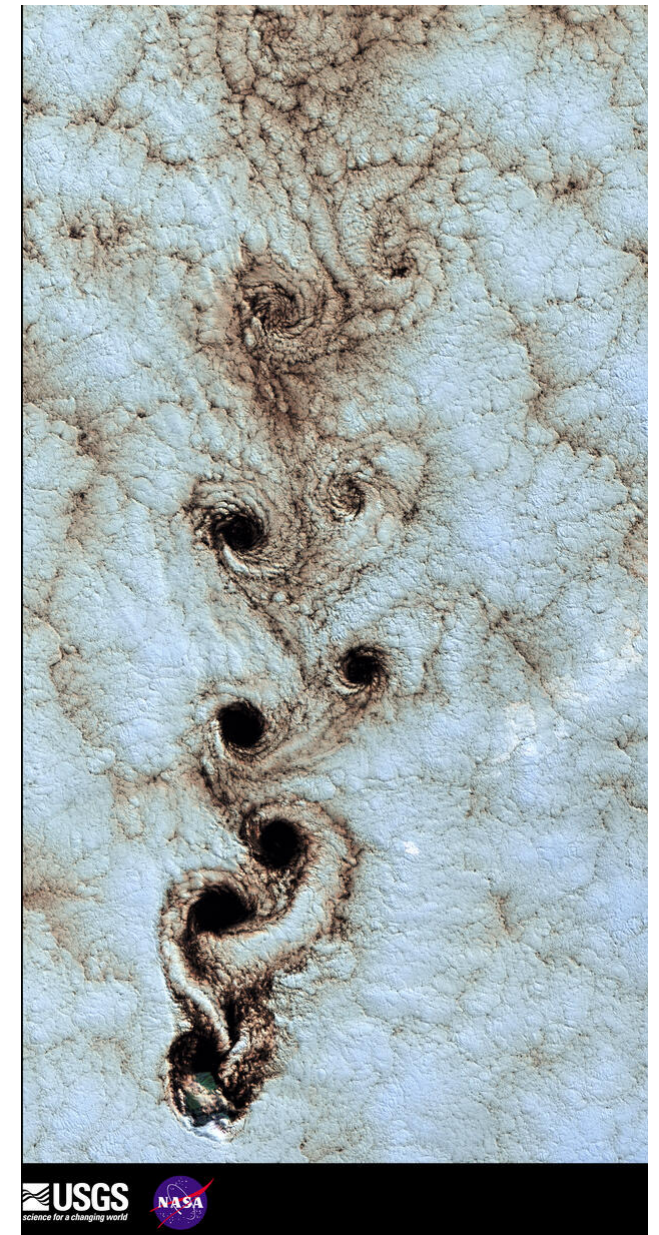
ODEs on manifolds are common



(a) Power grid
(multiple time scales)

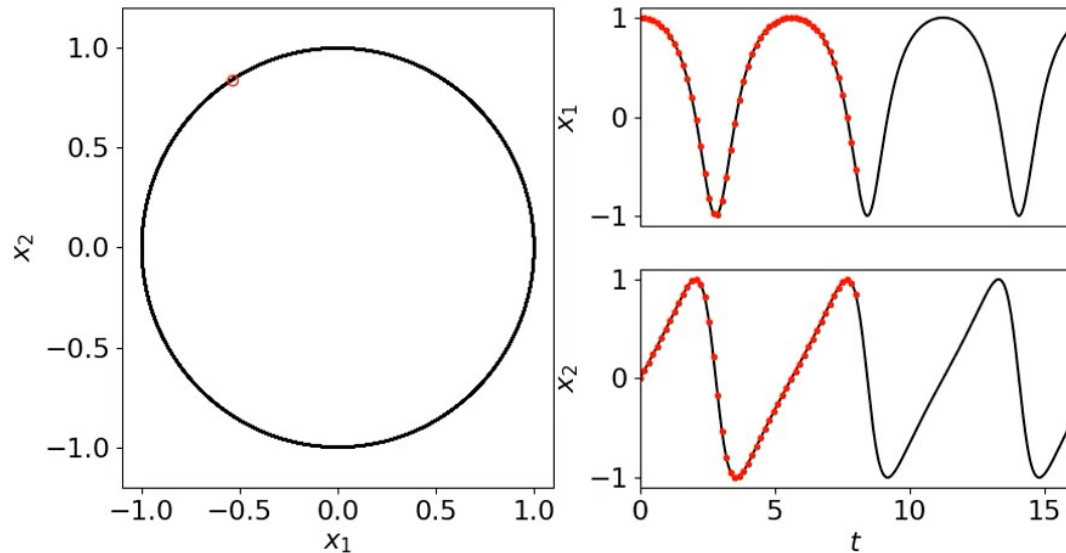


(b) Robotic system
(algebraic constraints)



(c) Fluid dynamics
(inertia manifold) ²

Learning and solving such ODEs is non-trivial



Simple example

$$\dot{\mathbf{x}} = \mathbf{f}(\mathbf{x}), \mathbf{x} \in M$$

Manifold: M

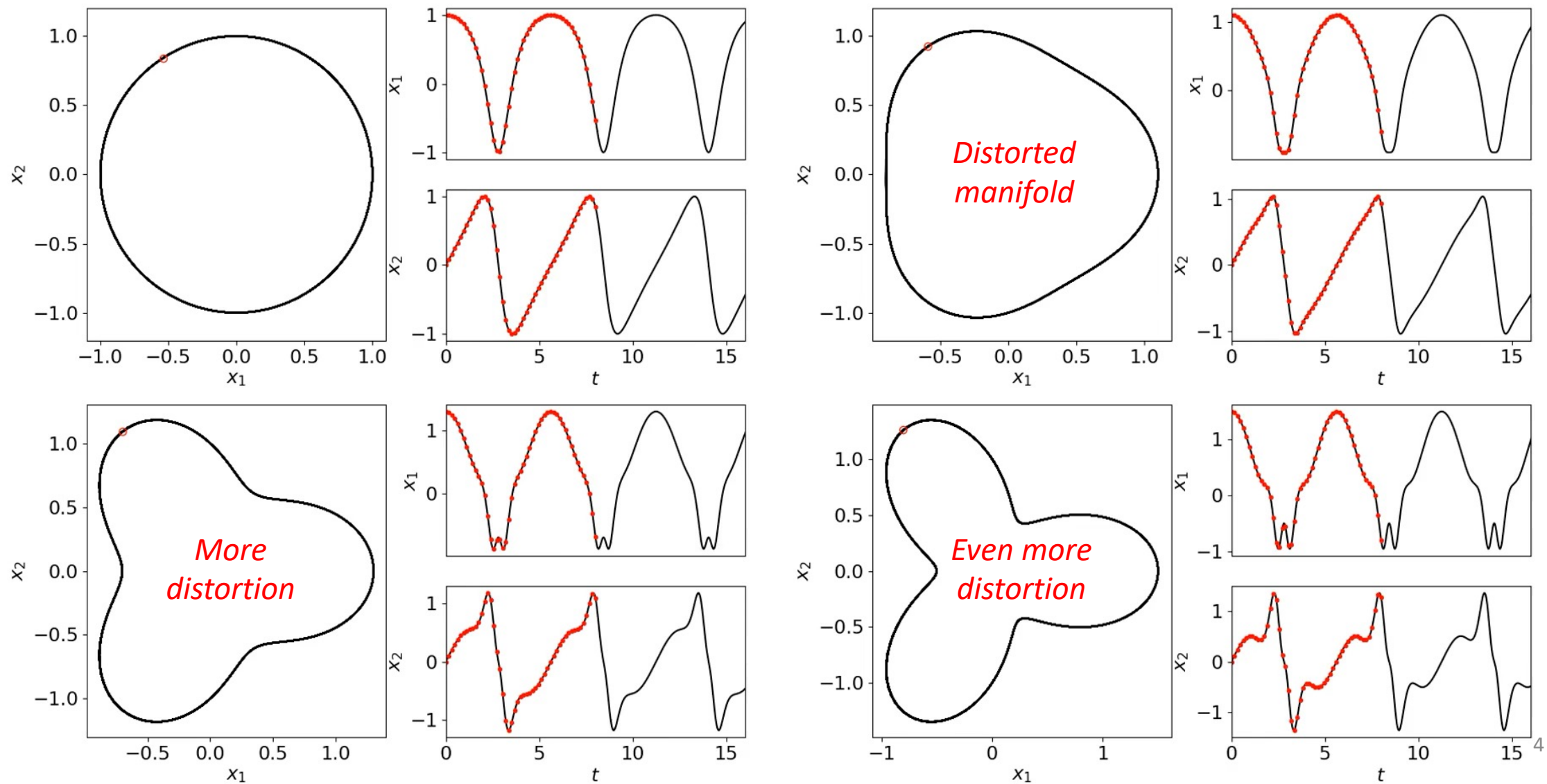
- Intrinsically 1D
- Embedded in 2D

Question:

Given trajectory data $\{(t_i, \mathbf{x}_i)\}_{i=1}^N$

- How to learn $\mathbf{f}(\mathbf{x})$, which should be a **vector field** on M ?
- How to solve $\dot{\mathbf{x}} = \mathbf{f}(\mathbf{x})$, so that the solution **stays** on M ?

Learning and solving such ODEs is non-trivial



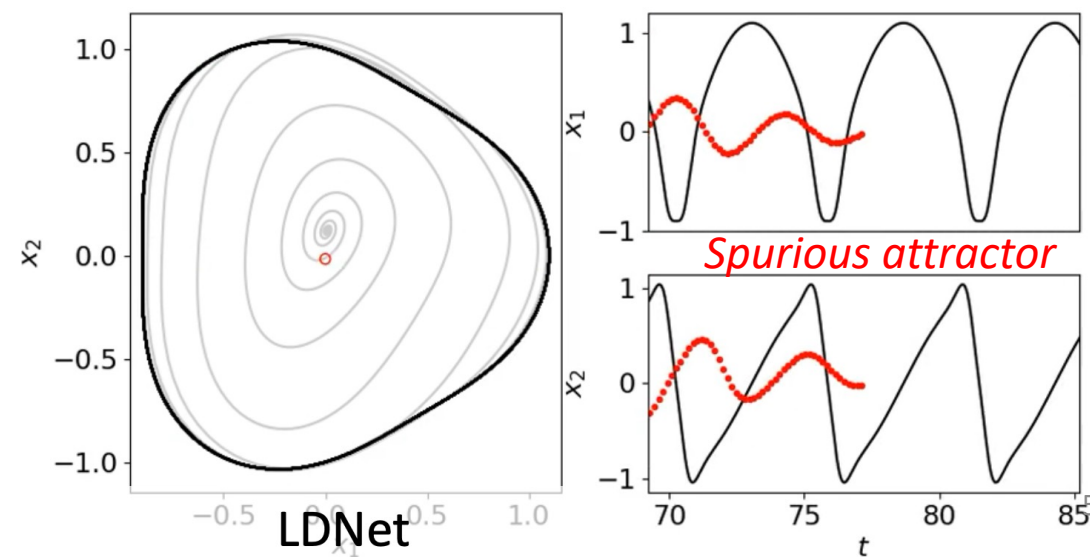
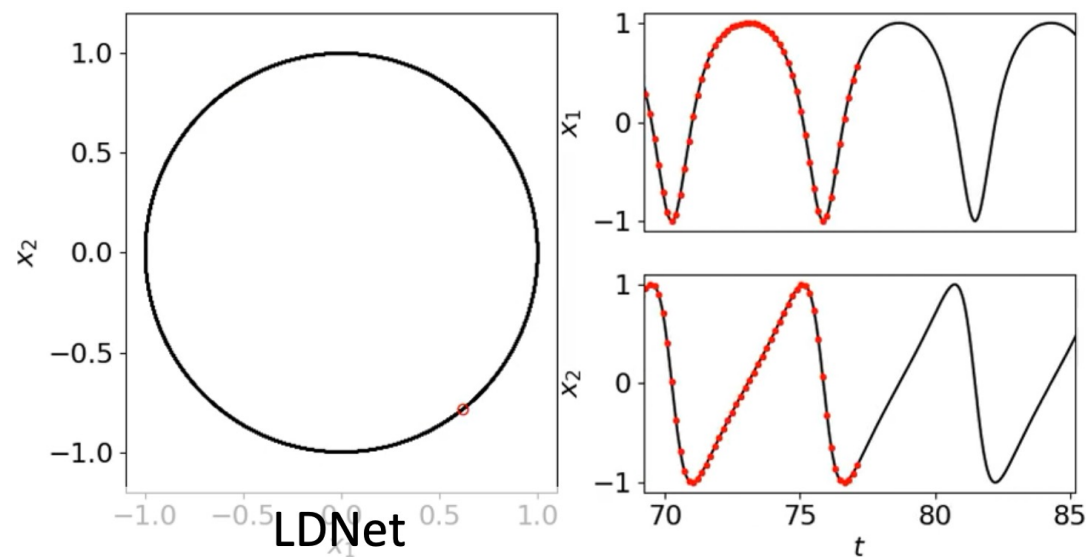
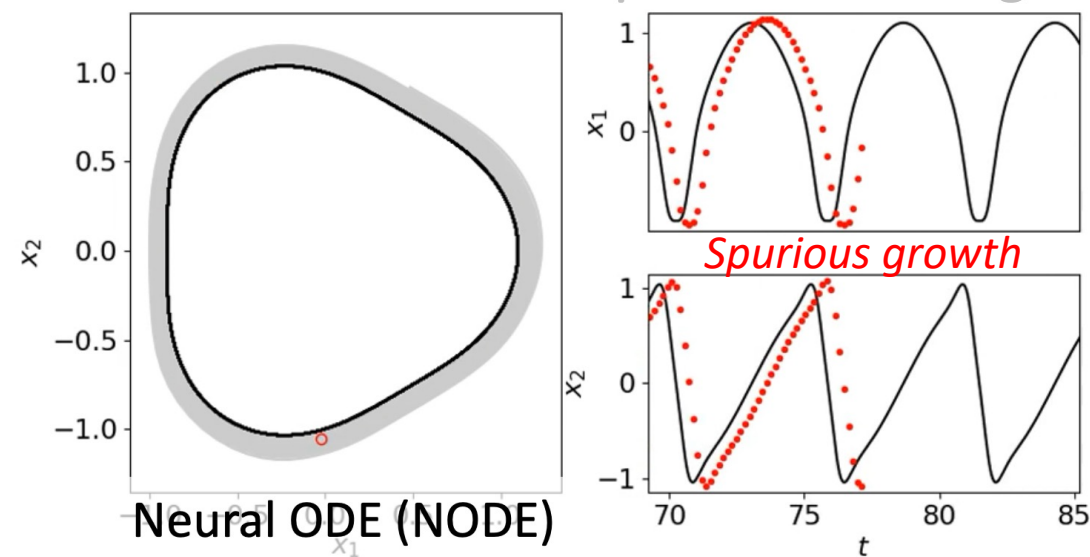
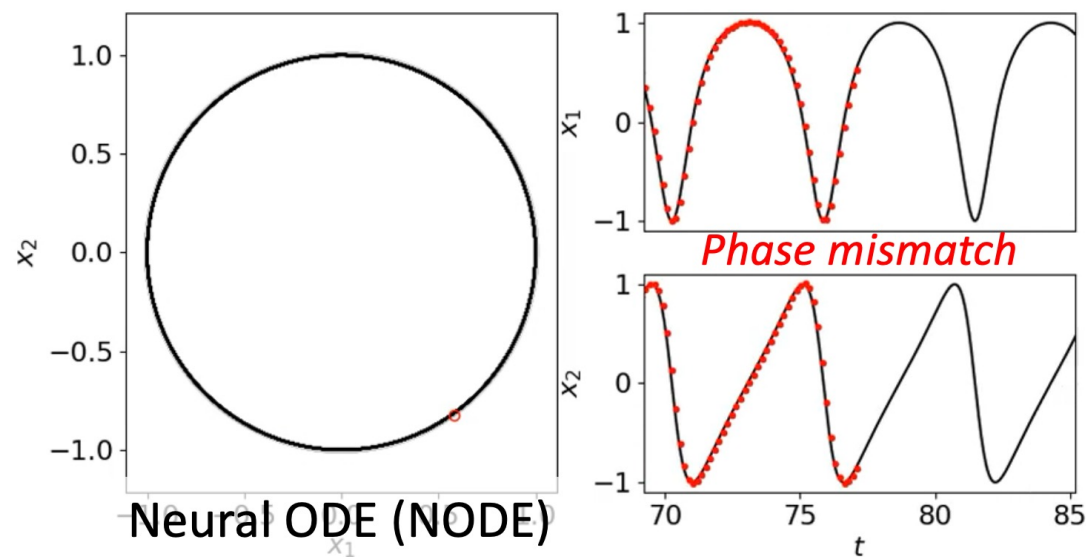
Challenges illustrated – 1/2

#1 Suboptimal compression

#2 Unconstrained dynamics

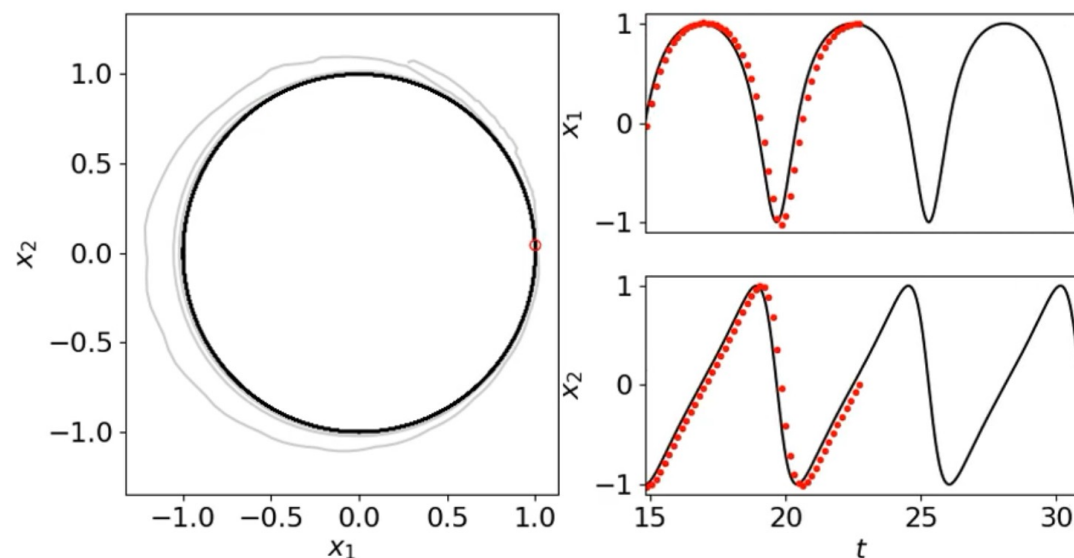
#3 Vanilla time integrator

#4 Expensive training



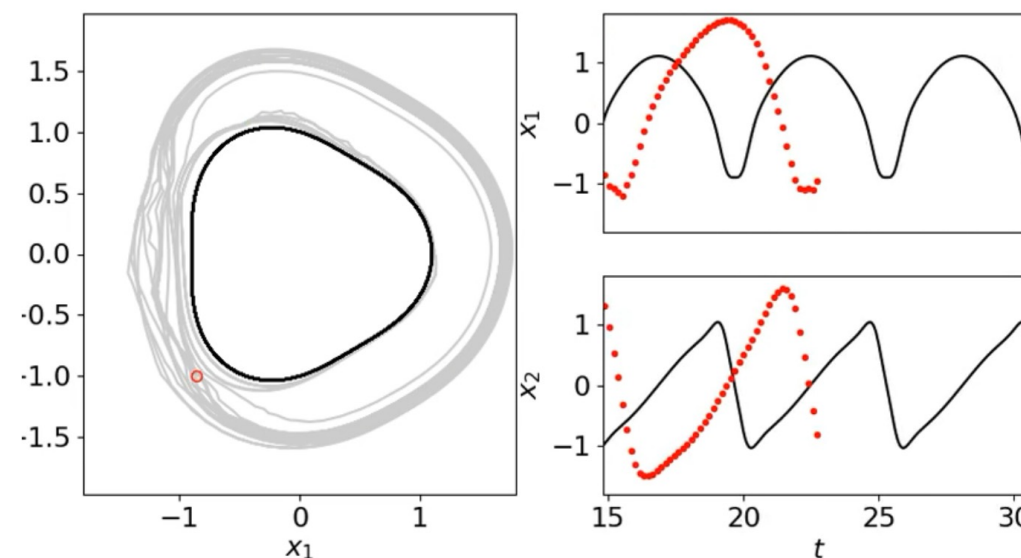
Challenges illustrated – 2/2

- #1 Suboptimal compression
- #2 Unconstrained dynamics
- #3 Vanilla time integrator
- #4 Expensive training



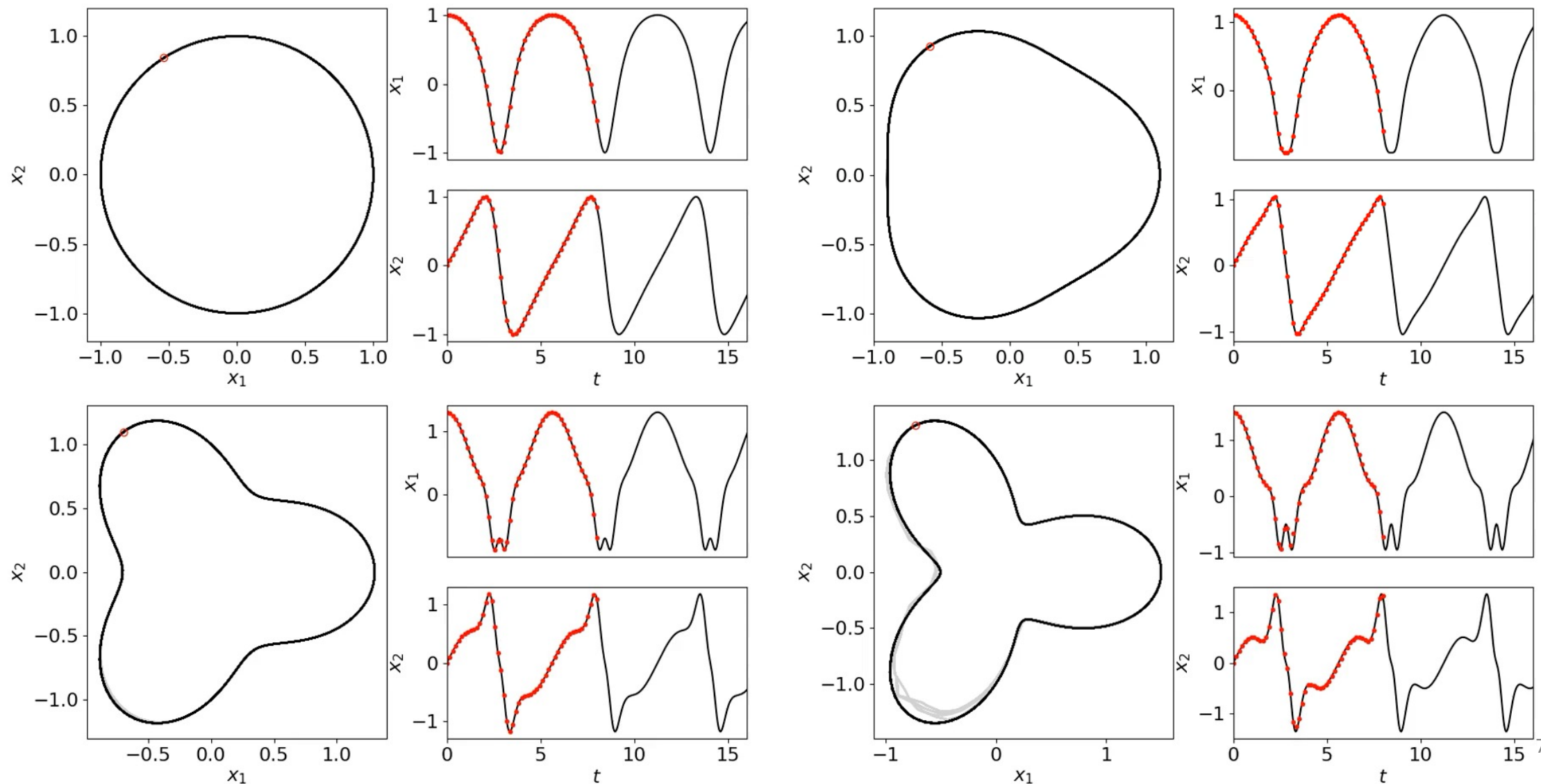
Correct dynamics
but solution by RK2

→ *Violation of
geometrical constraints*



Our method to resolve all

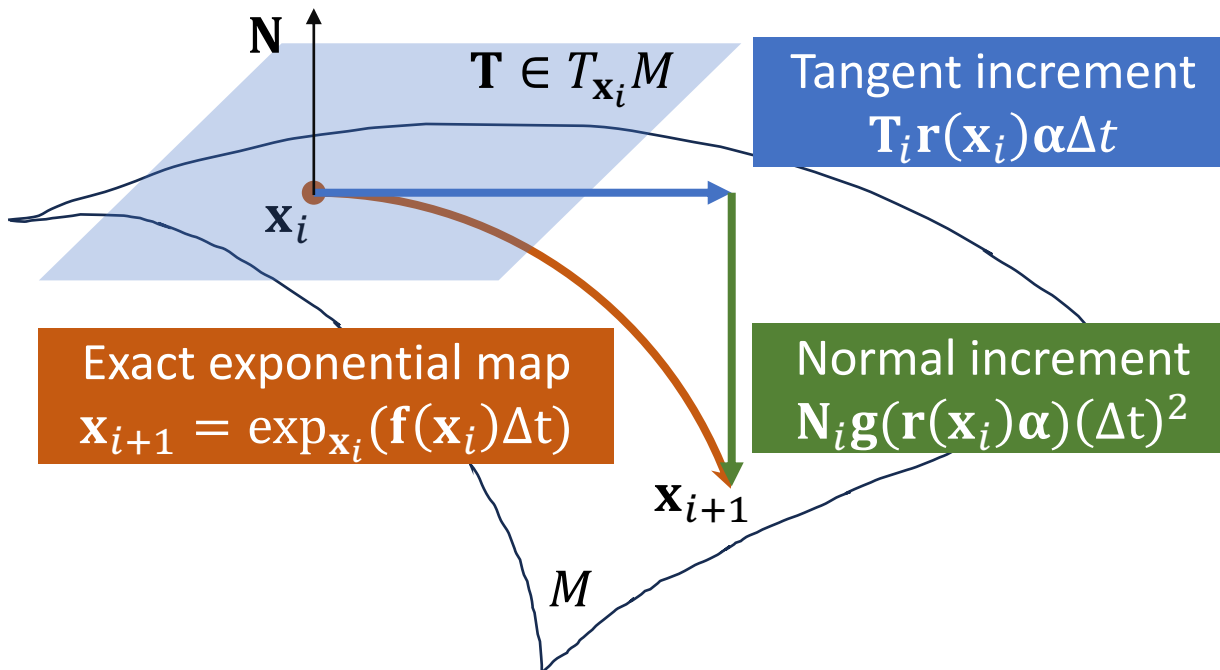
- #1 Suboptimal compression
- #2 Unconstrained dynamics
- #3 Vanilla time integrator
- #4 Expensive training



Our solution

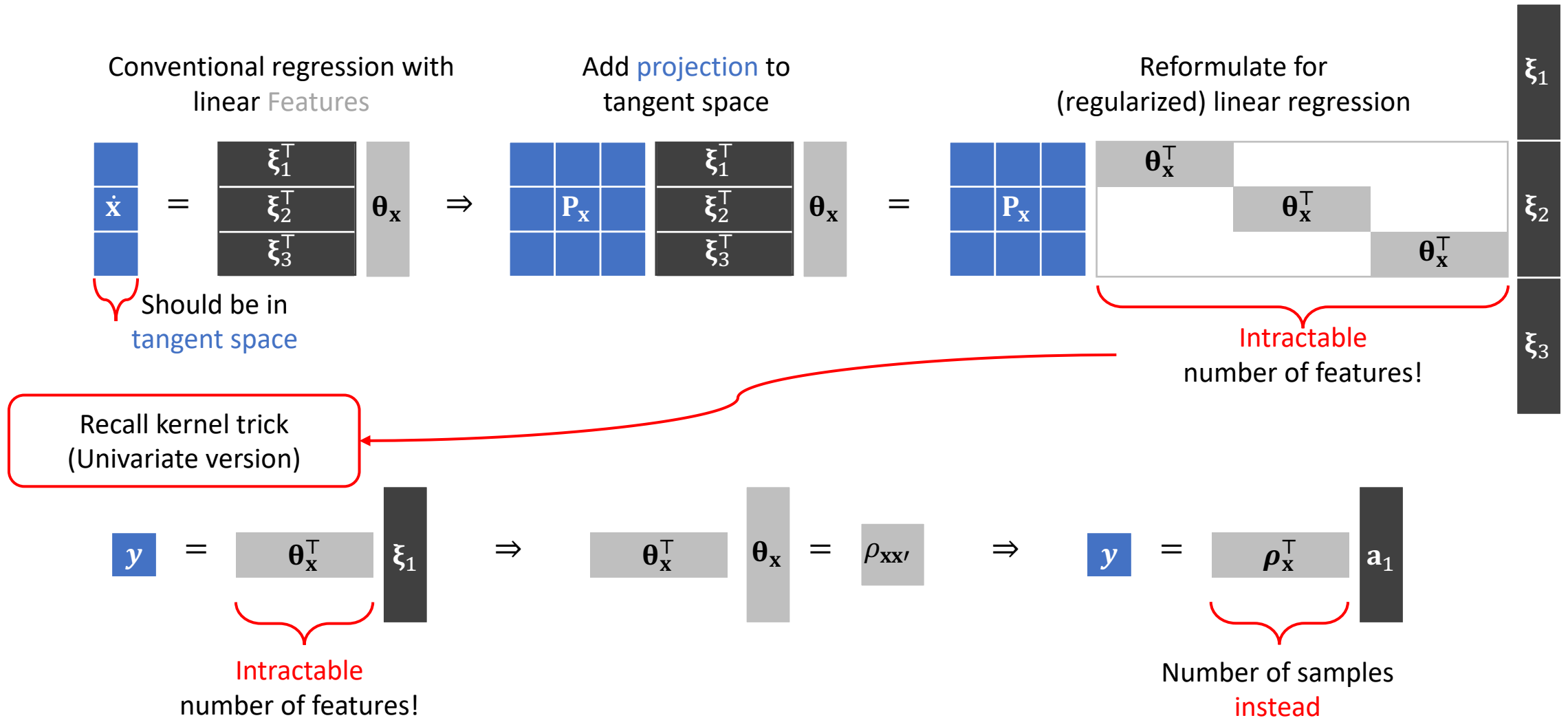
Identity of exponential map:

$$\mathbf{x}_{i+1} = \exp_{\mathbf{x}_i}(\mathbf{f}(\mathbf{x}_i)\Delta t) = \mathbf{x}_i + \underbrace{\mathbf{T}_i \mathbf{T}_i^\top (\mathbf{x}_{i+1} - \mathbf{x}_i)}_{\text{Tangent: } \mathbf{f}(\mathbf{x}_i)\Delta t} + \underbrace{\mathbf{N}_i \mathbf{N}_i^\top (\mathbf{x}_{i+1} - \mathbf{x}_i)}_{\text{Normal: } O((\Delta t)^2)}$$



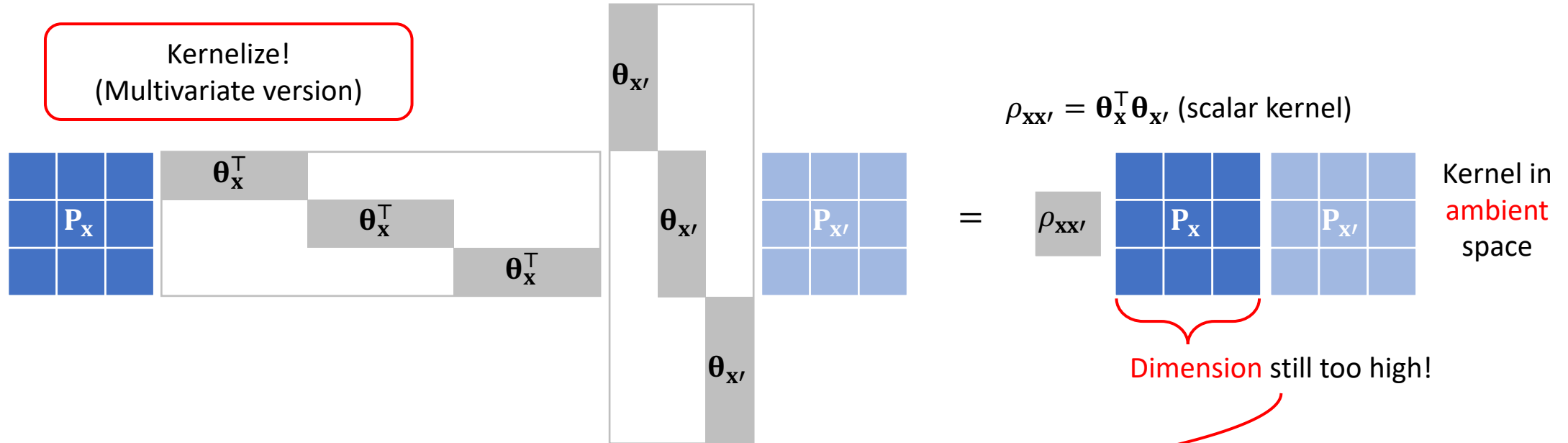
- *Ingredient 1:* Solves #1 and #2
Geometric Multivariate
Kernel Ridge Regression (GMKRR)
- *Ingredient 2:* Solves #3
Normal Correction (NC) by
Generalized Moving Least Squares (GMLS)
- *Ingredients 1+2:* Solves #4

Ingredient #1: Geometric Multivariate KRR

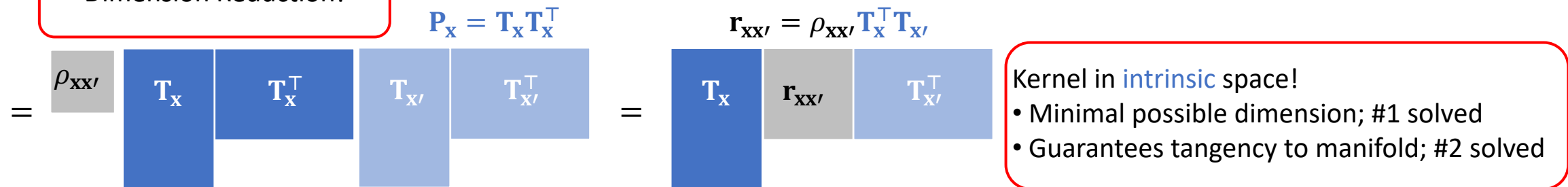


Ingredient #1: Geometric Multivariate KRR

Kernelize!
(Multivariate version)

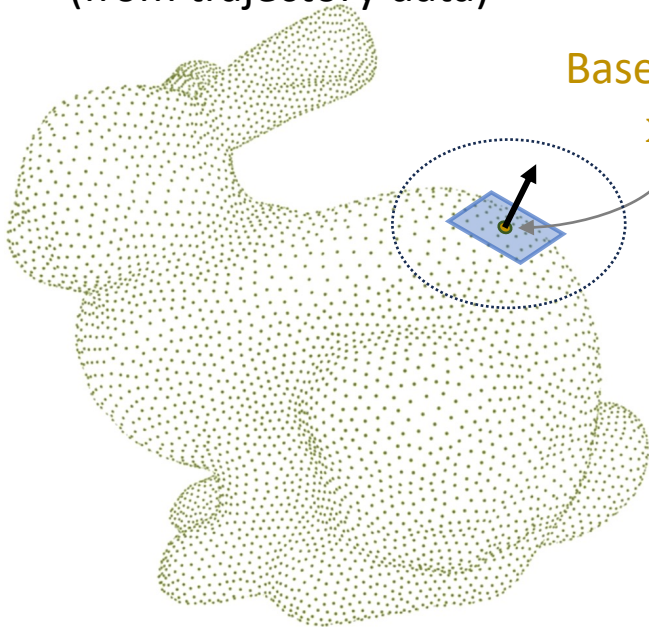


Dimension Reduction!

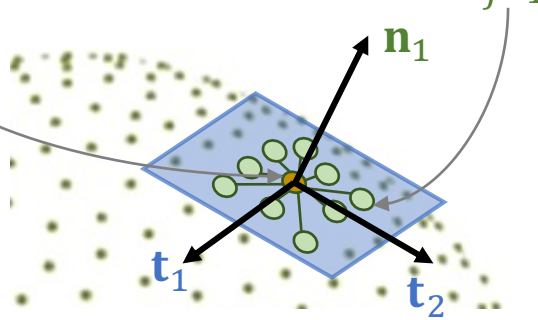


Ingredient #2: Normal Correction

- ① Point cloud on manifold
(from trajectory data)

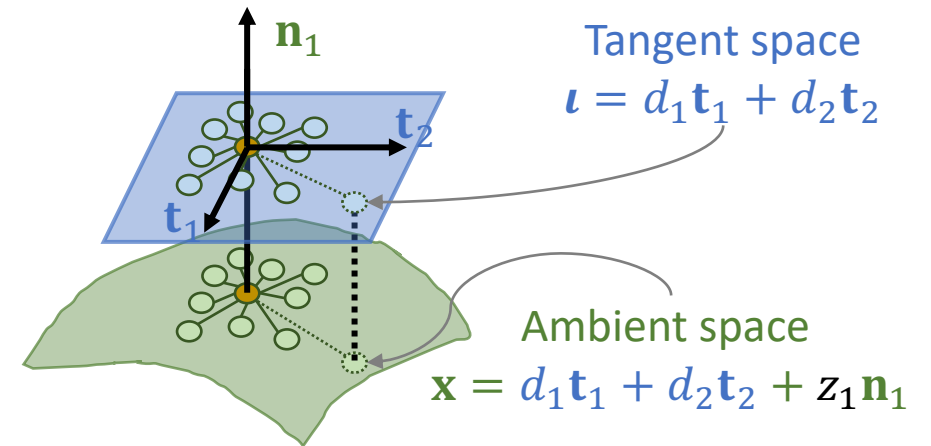


- ② Form local structure
K-Nearest Neighbor
points $D_{\mathbf{x}_i} = \{\mathbf{x}_{i,j}\}_{j=1}^K$



Basis $[\mathbf{t}_1, \mathbf{t}_2]$ for
tangent space at \mathbf{x}_i
(by Local SVD)

- ③ Normal correction by polynomial fit



GMLS fit by $D_{\mathbf{x}_i}$
 $z_1 = g_{poly}(d_1, d_2)$

Summary of algorithm

Theory: $\mathbf{x}_{i+1} = \exp_{\mathbf{x}_i}(\mathbf{f}(\mathbf{x}_i)\Delta t) = \mathbf{x}_i + \underbrace{\mathbf{T}_i \mathbf{T}_i^\top (\mathbf{x}_{i+1} - \mathbf{x}_i)}_{\text{Tangent: } \mathbf{f}(\mathbf{x}_i)\Delta t} + \underbrace{\mathbf{N}_i \mathbf{N}_i^\top (\mathbf{x}_{i+1} - \mathbf{x}_i)}_{\text{Normal: } O((\Delta t)^2)}$

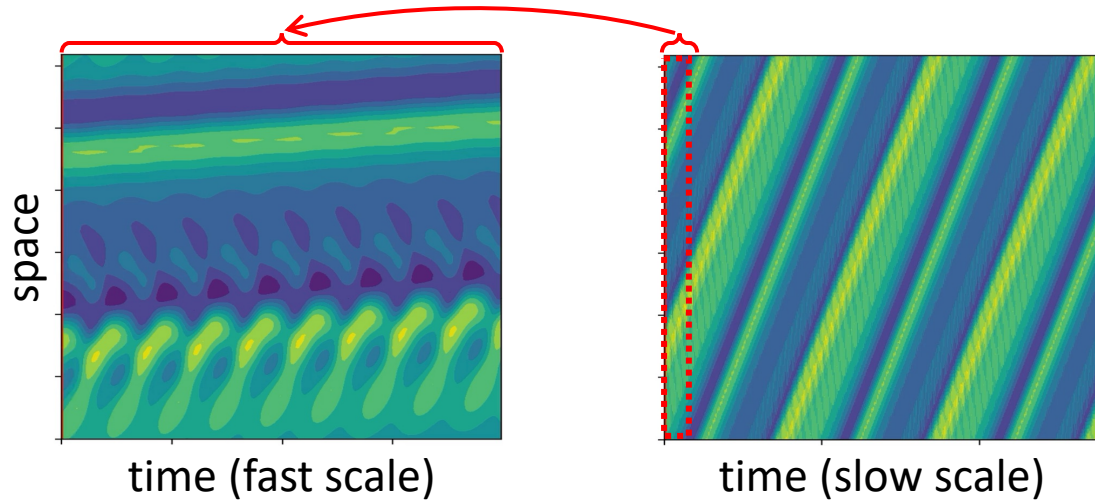
Algorithm: $\hat{\mathbf{x}}_{\epsilon,i+1} = \hat{\mathbf{x}}_{\epsilon,i} + \Delta t \mathbf{f}_\epsilon(\hat{\mathbf{x}}_{\epsilon,i}) + (\Delta t)^2 \hat{\mathbf{N}}_{\epsilon,i} \hat{g}(\hat{\mathbf{T}}_{\epsilon,i}^\top \mathbf{f}_\epsilon(\hat{\mathbf{x}}_{\epsilon,i}))$

Geometric Multivariate
Kernel Ridge Regression
Normal Correction by
Generalized Moving Least Squares

Convergence: $\sqrt{\mathbb{E}_\mu [\|\mathbf{x}_n - \hat{\mathbf{x}}_{\epsilon,n}\|^2]} \leq C \left(\epsilon + \Delta t \left(\frac{\log(N)}{N} \right)^{\frac{\ell}{d}} \right)$

↙ Expected error at $t = n\Delta t$
↙ Error of learned vector field
 ↙ Step size (first-order accurate)
 ↙ # of data points
 ↗ $\frac{\text{Manifold smoothness}}{\text{Intrinsic dimension}}$

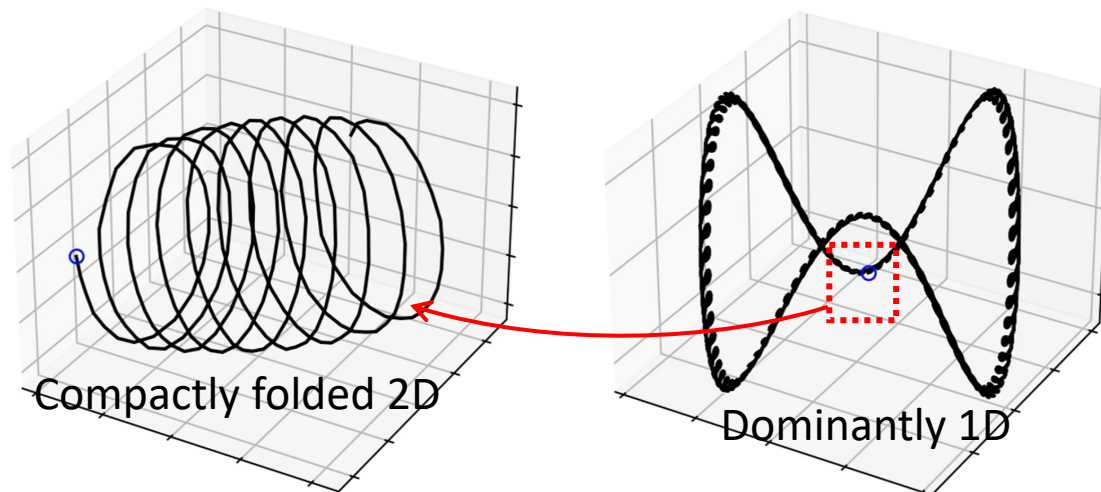
Numerical demonstrations



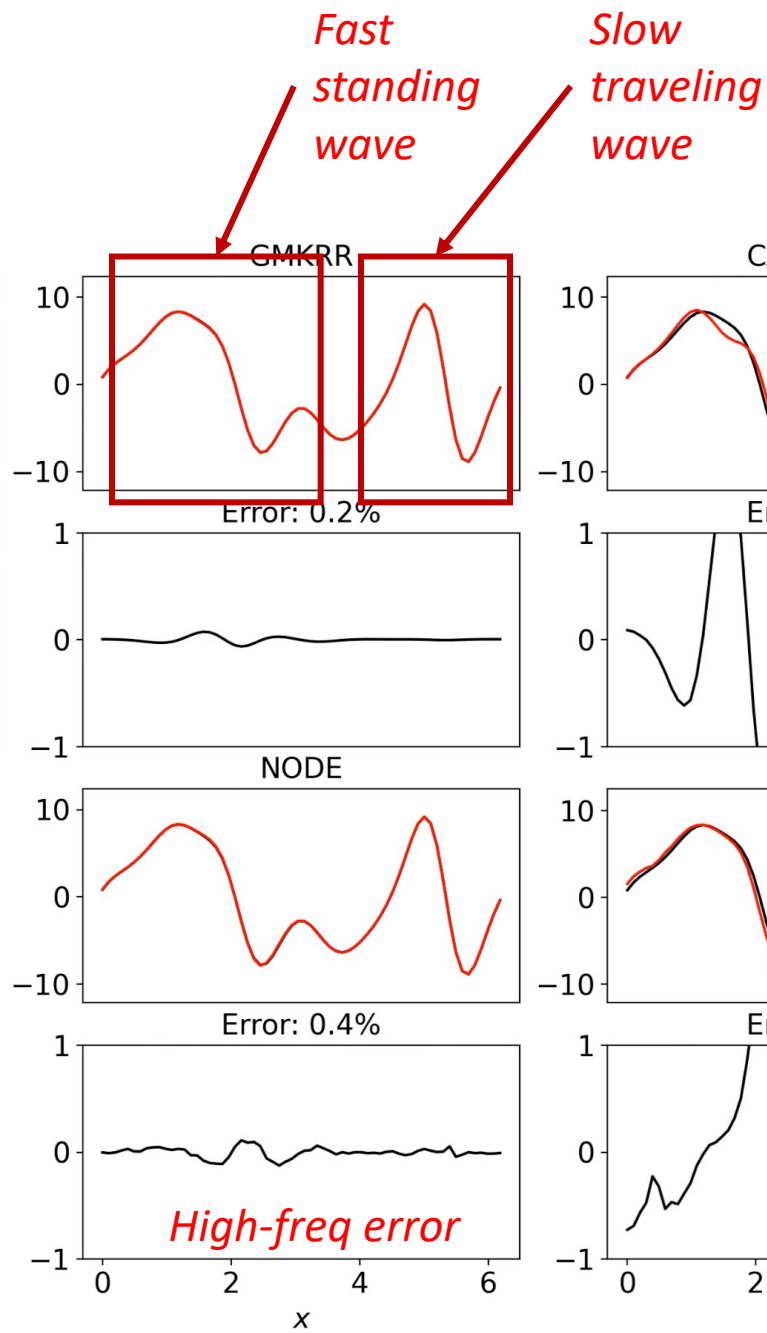
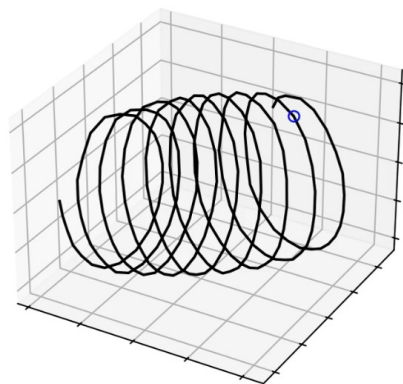
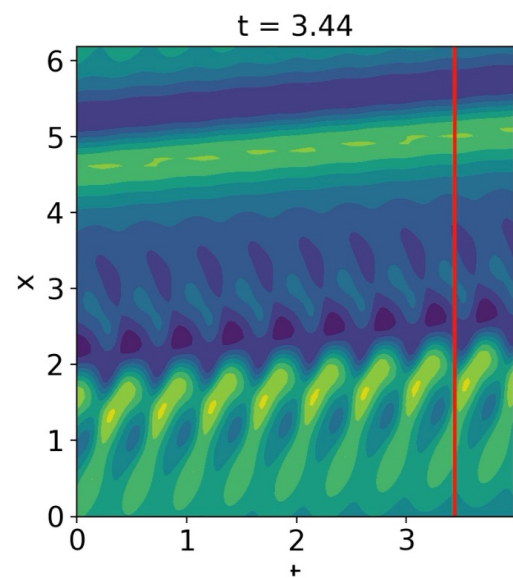
Example: 1D Kuramoto-Sivashinsky

$$u_t + uu_x + u_{xx} + \nu u_{xxxx} = 0$$

- Inertia manifold with $\nu = \frac{4}{87}$ and periodic BC
- Time scale disparity: fast and slow
- Intrinsic dimension: 2
- Ambient dimension: 64

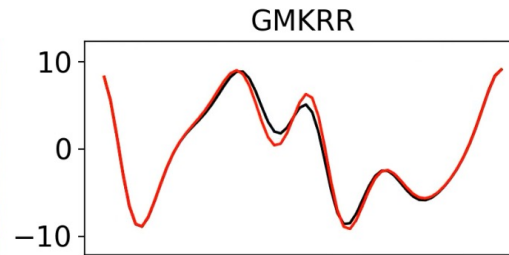
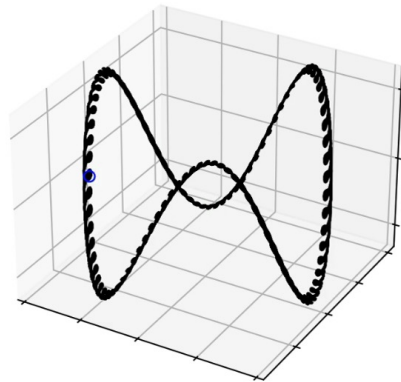
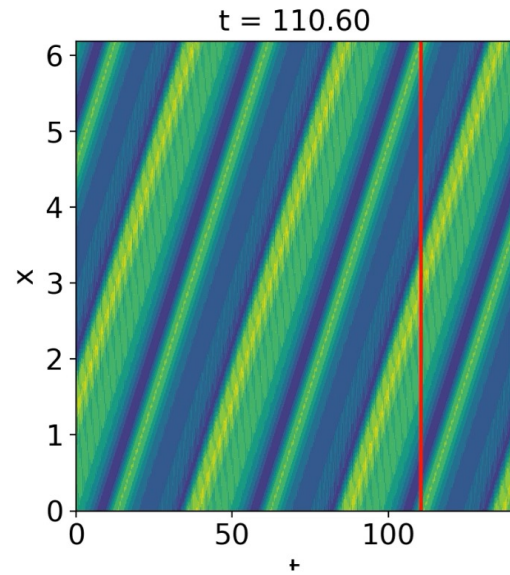


Fast Dynamics

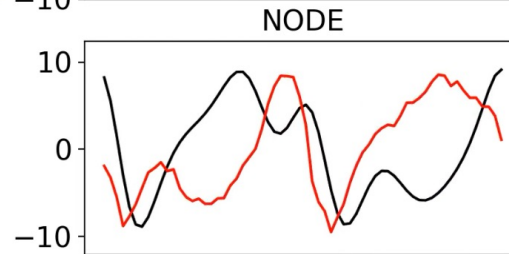
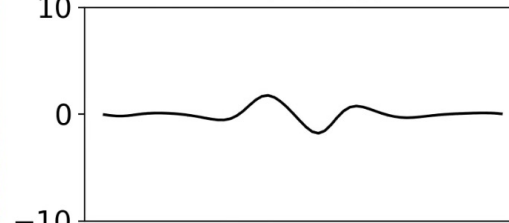


*Accumulation of
phase mismatch*

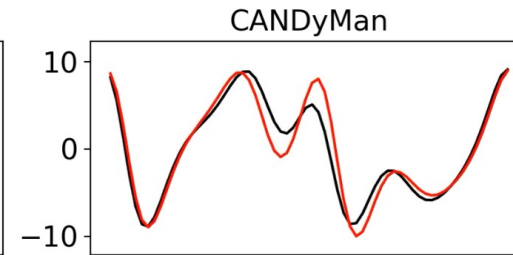
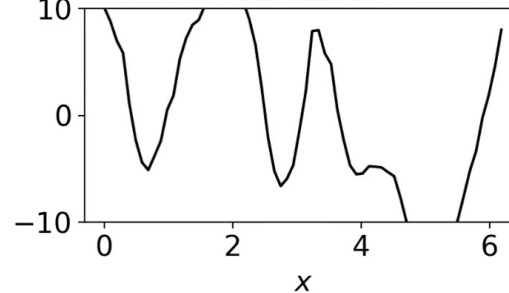
Slow Dynamics



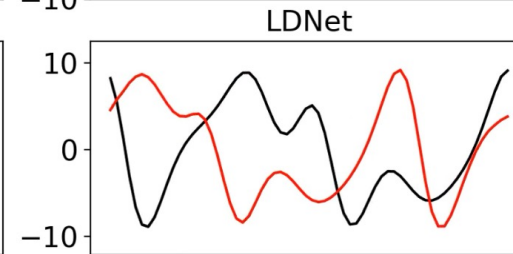
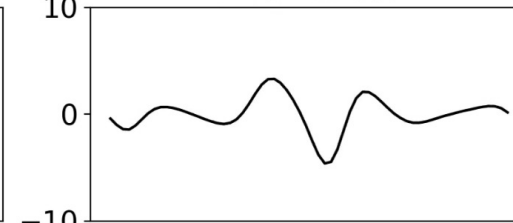
Error: 5.2%



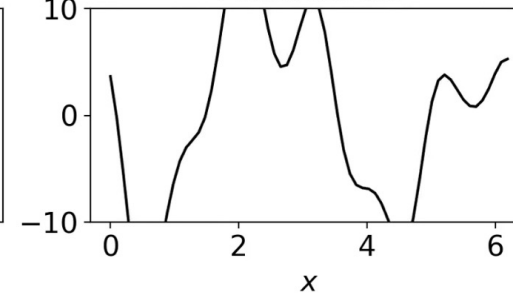
Error: 60.5%



Error: 12.5%



Error: 68.4%



*Loss of fine structure
at fast time scale*

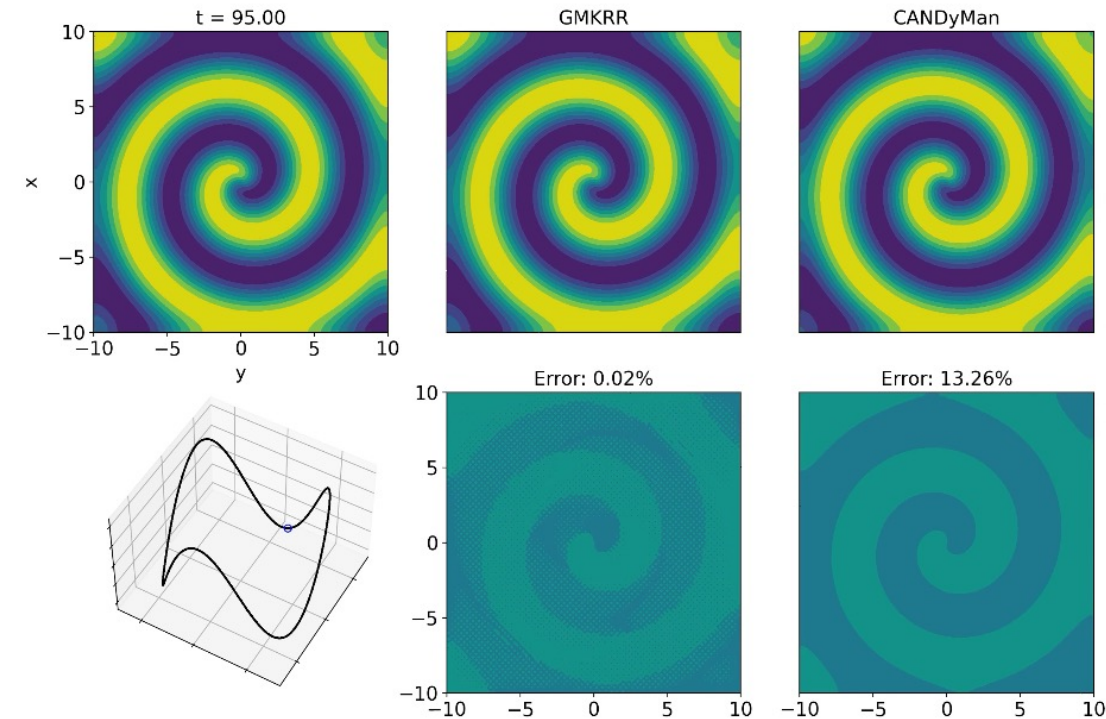
*Complete loss of
phase and shape*

Summary

- #1 Optimal compression – up to intrinsic dimension
- #2 Constrained dynamics – by operator-valued kernel
- #3 Time integrator – preserving geometry
- #4 Efficient training – no NN's at all

CASE	MODEL	Training Time (s)	Pred. Time (s)	RMSE	Maximum Error
KS Beating	CANDyMan	48.04	0.6703	0.2744	2.130
	GMKRR	0.01367	0.5133	0.02549	0.1972
KS Travelling	CANDyMan	70.10	19.44	2.391	15.22
	NODE	395.6	4.166	6.690	22.14
	LDNet	77.87	13.53	7.600	22.46
	GMKRR-Full	11.68	20.82	1.604	12.45
	GMKRR-FFT	0.04550	24.41	0.3671	3.088
Reaction-Diffusion	CANDyMan	265.8	14.59	0.1797	0.5517
	GMKRR-Full	3.723	175.4	7.394E-4	2.959E-3
	GMKRR-PCA-T0	0.01953	4.786	7.399E-4	2.961E-3
	GMKRR-PCA-T4	0.1187	8.5855	1.216E-4	1.339E-3

Quantitative comparison



Reaction-diffusion
Ambient dim.: 20402



PennState



ICLR

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Paper and Code

