

Geometric deep learning - from AI to gauge theory, and back -

Daniel Persson

Department of Mathematical Sciences
Chalmers University of Technology
University of Gothenburg

**Quantum gravity:
The sound of symmetry**



Hermannfest

AEI Potsdam
Sept 13, 2022



Talk based on

“Geometric deep learning and equivariant neural networks”

By Gerken, Aronsson, Carlsson, Linander, Ohlsson, Petersson, **D.P.**

[arXiv: 2105.13926]

“Equivariance versus augmentation for spherical images”

By Gerken, Carlsson, Linander, Ohlsson, Petersson, **D.P.**

[arXiv: 2202.03990]

+ *work in progress*



Talk based on

“Geometric deep learning and equivariant neural networks”

By Gerken, Aronsson, Carlsson, Linander, Ohlsson, Petersson, **D.P.**

[arXiv: 2105.13926]

“Equivariance versus augmentation for spherical images”

By Gerken, Carlsson, Linander, Ohlsson, Petersson, **D.P.**

[arXiv: 2202.03990]

+ *work in progress*



Carlsson



Aronsson



Petersson



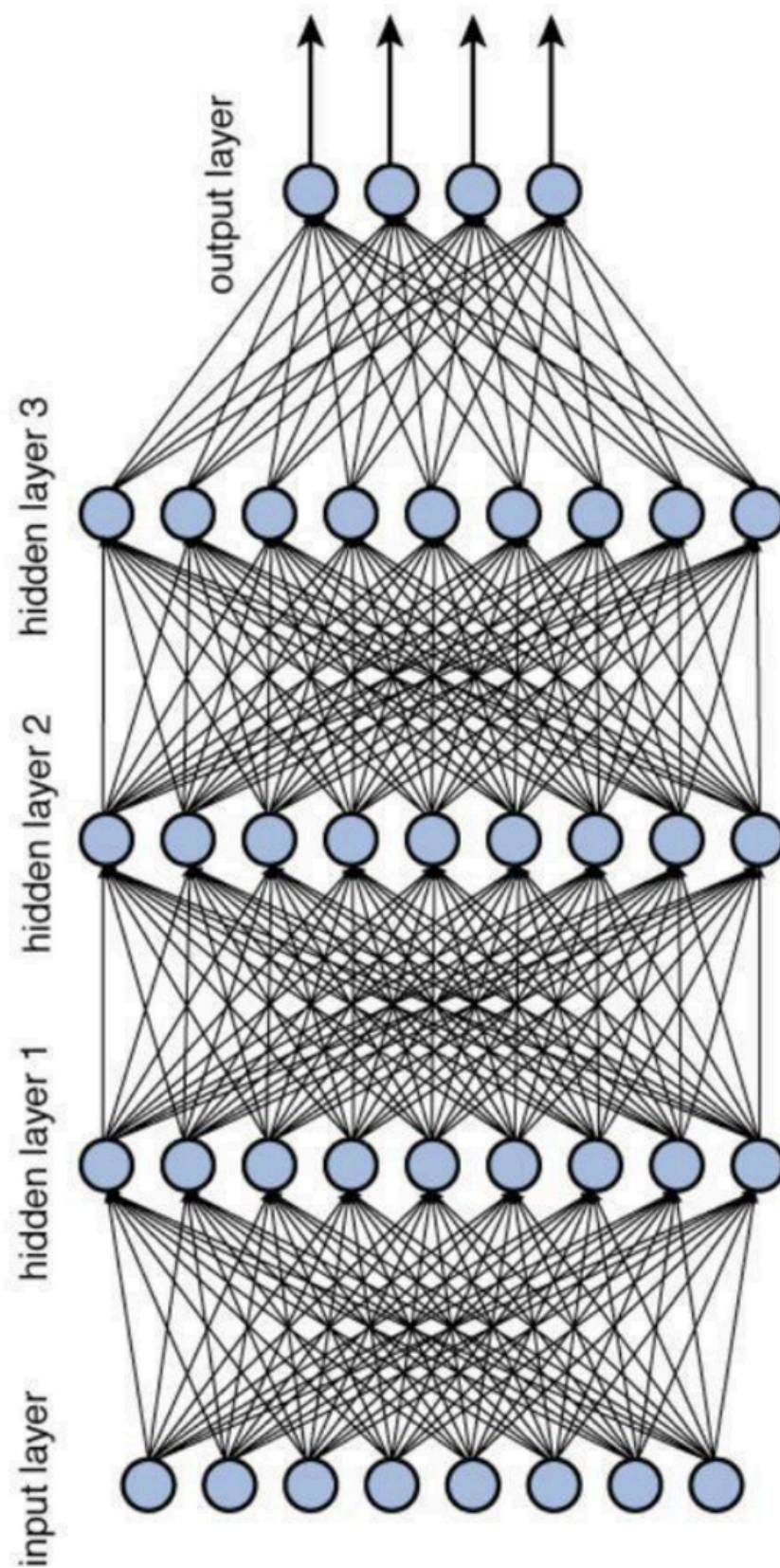
Gerken



Ohlsson



Linander



Artificial Intelligence:

Mimicking the intelligence or behavioural pattern of humans or any other living entity.

Machine Learning:

A technique by which a computer can “learn” from data, without using a complex set of different rules. This approach is mainly based on training a model from datasets.

Deep Learning:

A technique to perform machine learning inspired by our brain's own network of neurons.

Classification



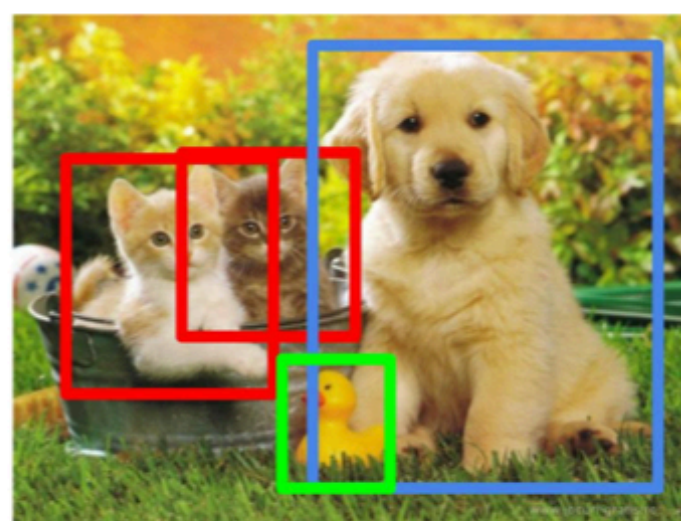
CAT

Classification + Localization



CAT

Object Detection



CAT, DOG, DUCK

Instance Segmentation



CAT, DOG, DUCK

Single object

Multiple objects



[Bild från thispersondoesnotexist.com]



[Bild från thispersondoesnotexist.com]



[Image from: <https://www.walleniuswilhelmsen.com/insights/the-future-of-mobility-whats-the-road-ahead-for-self-driving-vehicles>]

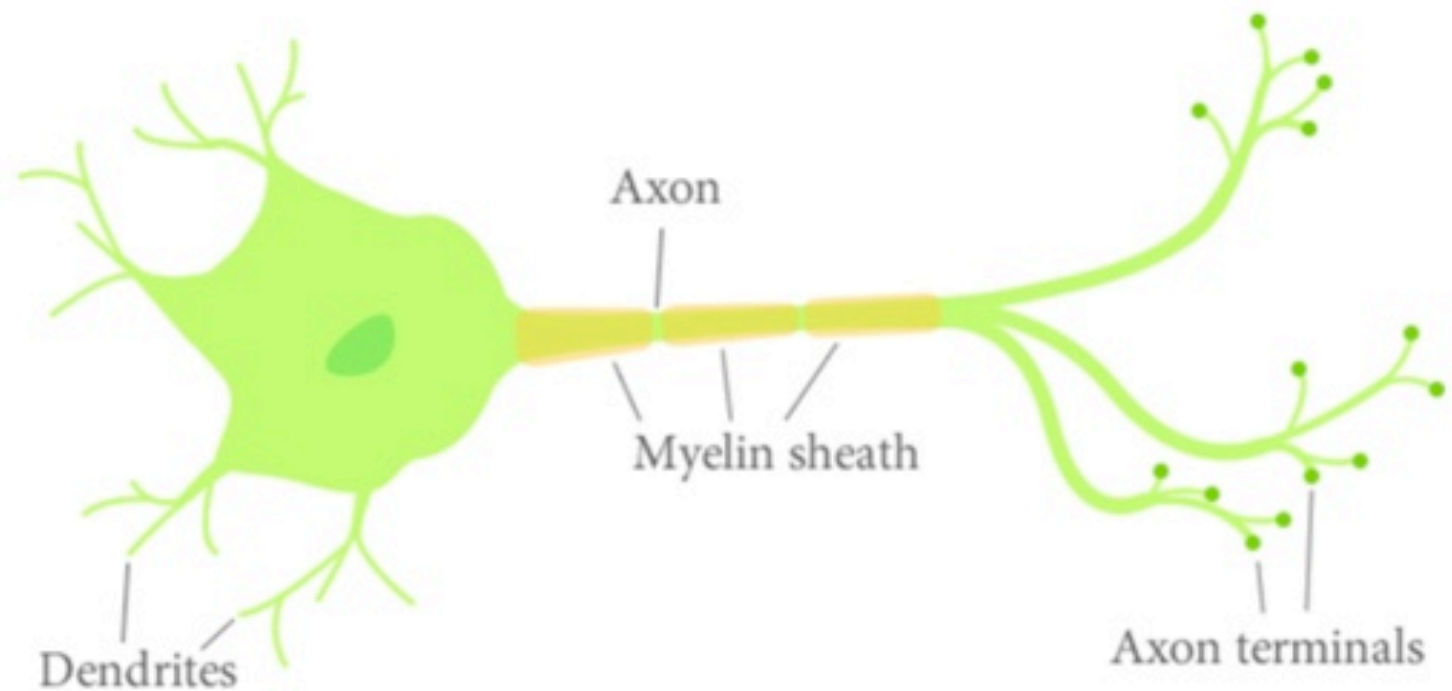
[Image from: <https://adigaskell.org/2018/10/15/how-good-is-machine-translation/>]



[Image from: <https://www.walleniuswilhelmsen.com/insights/the-future-of-mobility-whats-the-road-ahead-for-self-driving-vehicles>]

[Image from: <https://adigaskell.org/2018/10/15/how-good-is-machine-translation/>]

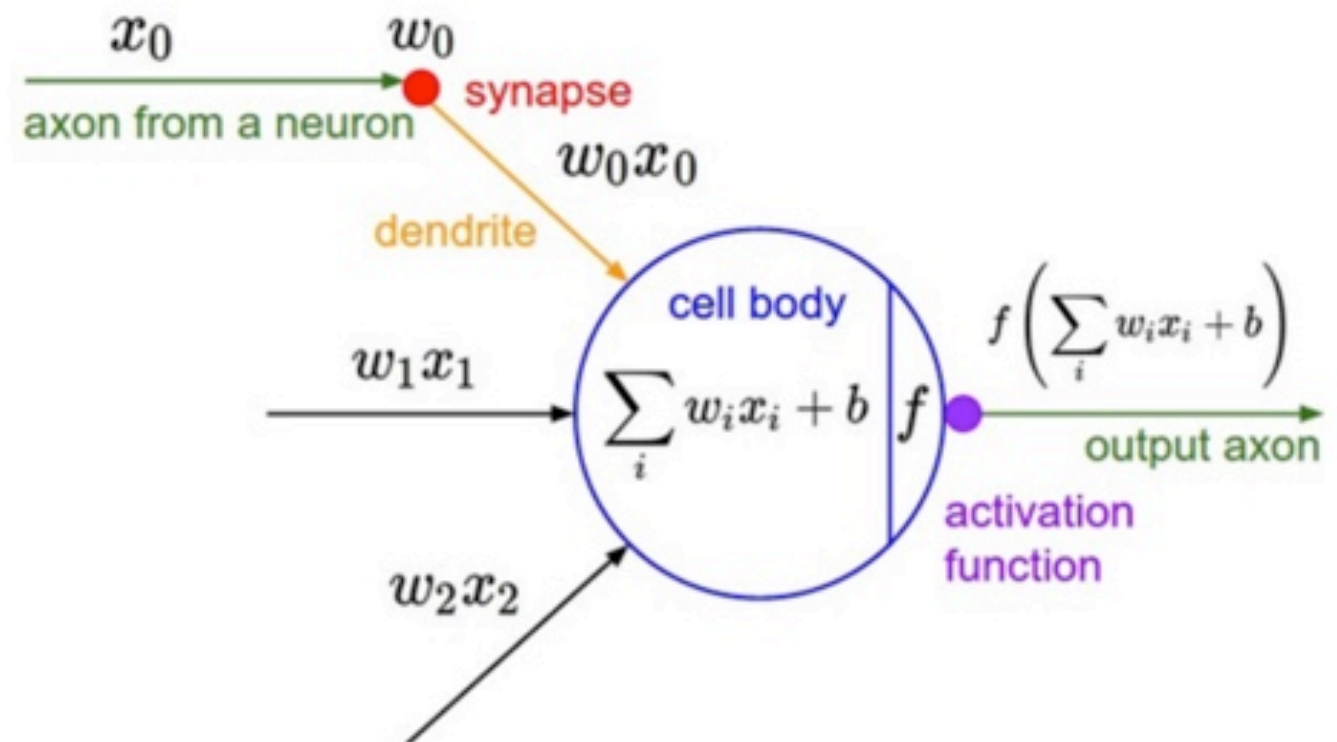
Real Neuron

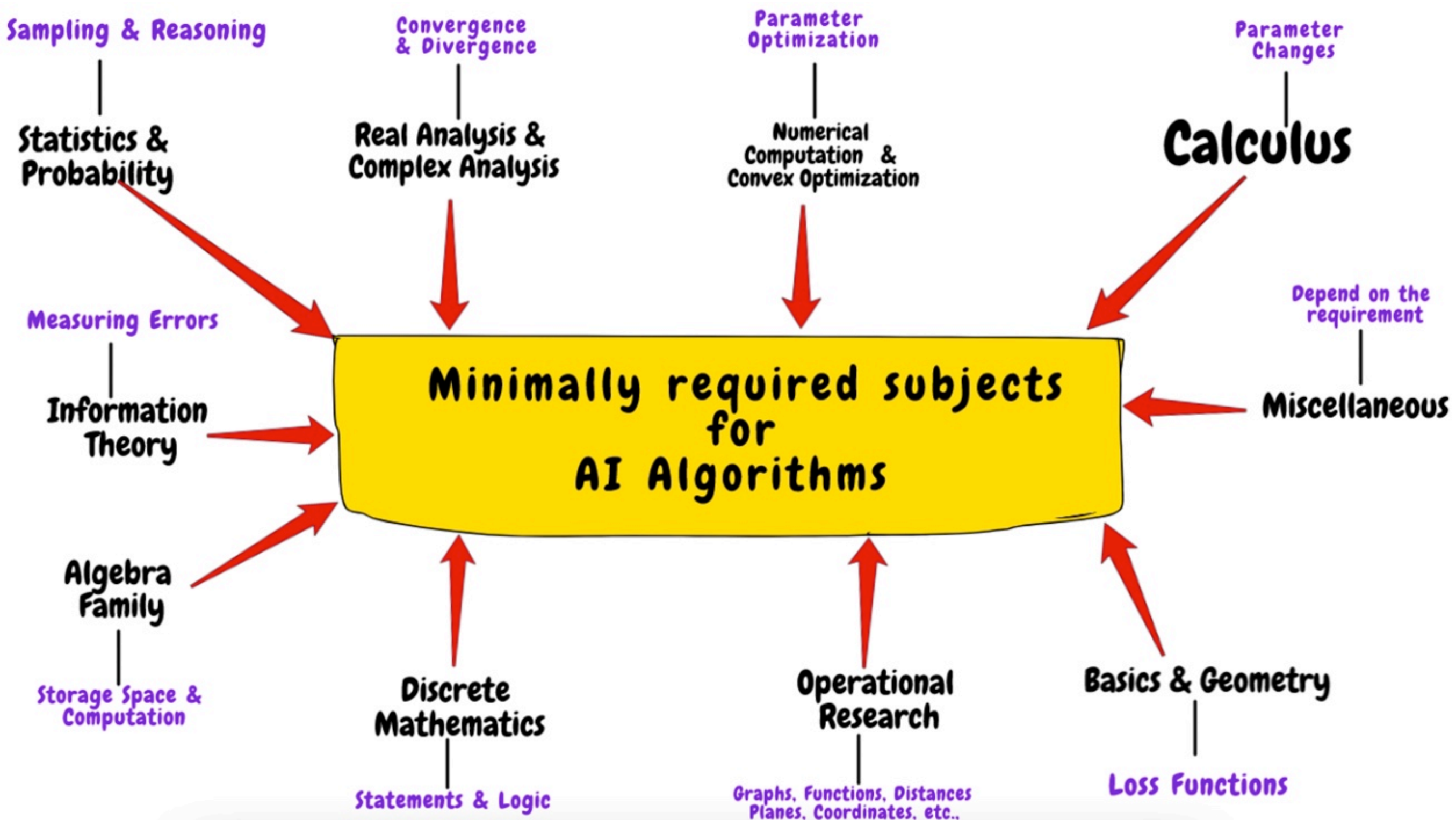


Artificial neuron:

1. Input layer
2. Hidden layer(s)
3. Output layer

Artificial Neuron

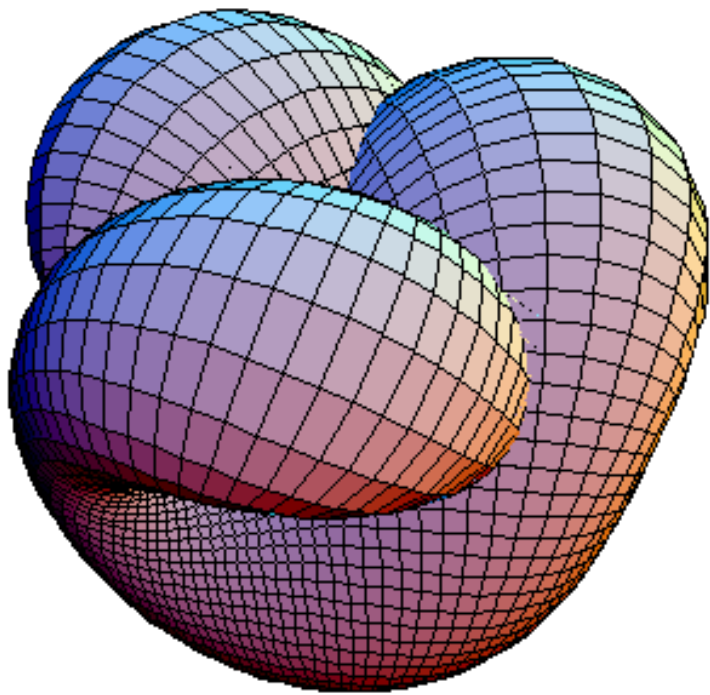




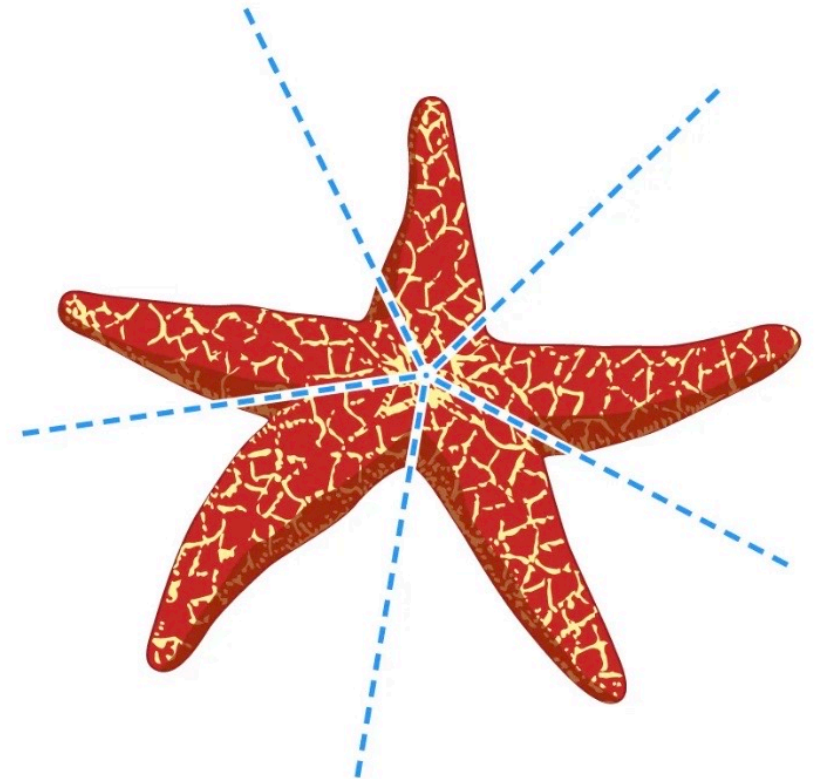
Geometric Deep Learning



What to do if the data is curved?



What to do if the data has symmetries?



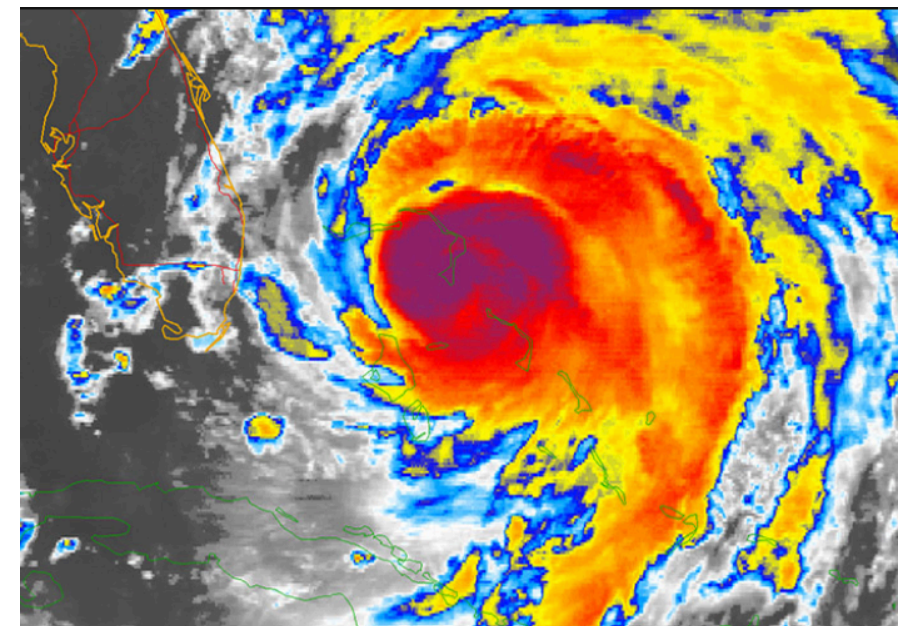
Geometric Deep Learning



Climate and weather data



Self-driving cars



Geometric Deep Learning



But also connections to mathematics:

Deep learning on manifolds [\[Cohen et al\]](#)

Sheaf neural networks [\[Bronstein et al\]](#)

Graph neural networks [\[LeCun et al\]](#)

And physics:

Lattice gauge theories [\[Favoni et al\]](#)

Supergravity and string vacua [\[He et al\]](#)[\[Berman, Fischbacher et al\]](#)

Topological phases of matter [\[in progress\]](#)

Convolutional Neural Networks

“Convolutional networks are simply neural networks that use convolution in place of general matrix multiplication in at least one of their layers.”

[Goodfellow, Bengio, Courville]

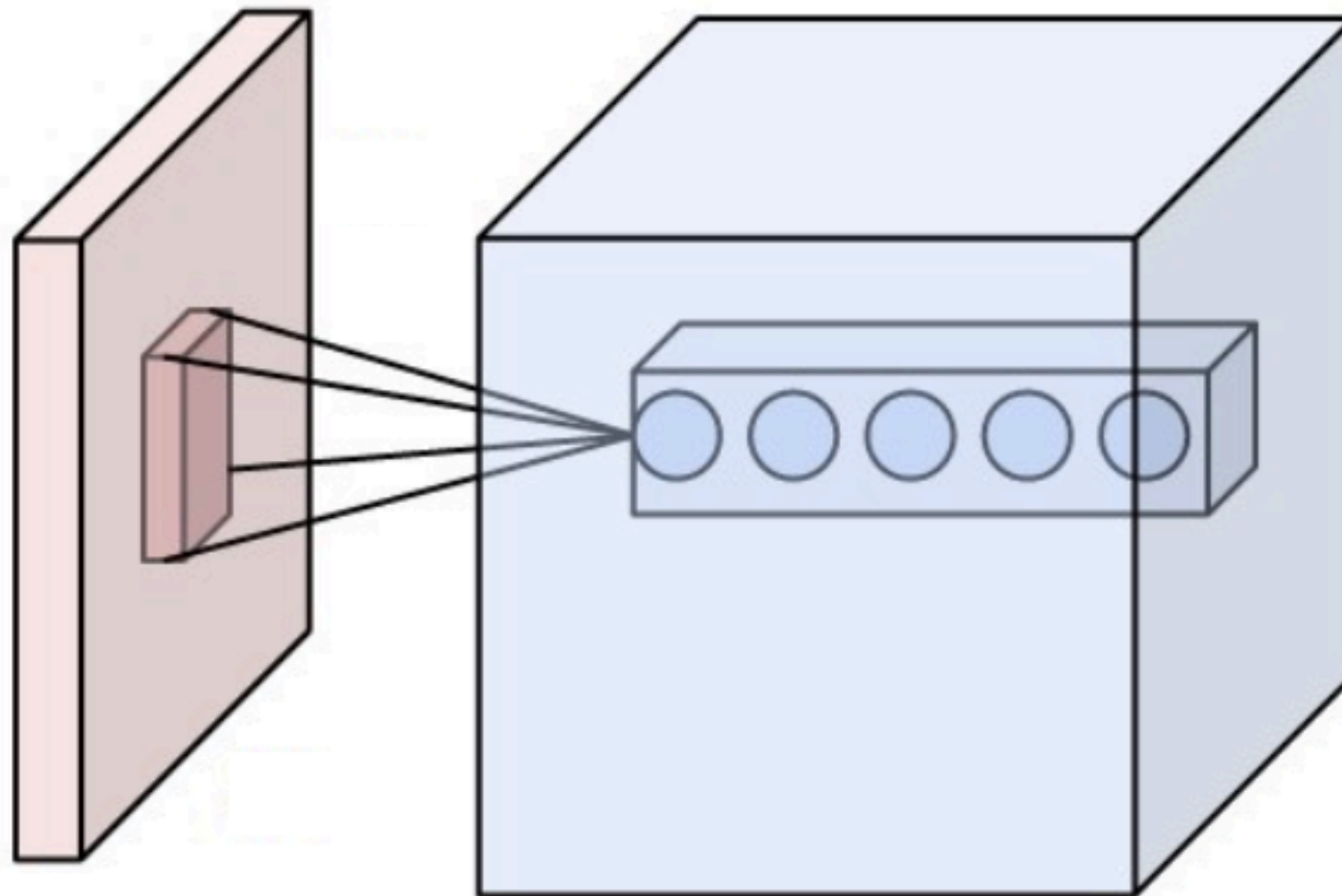
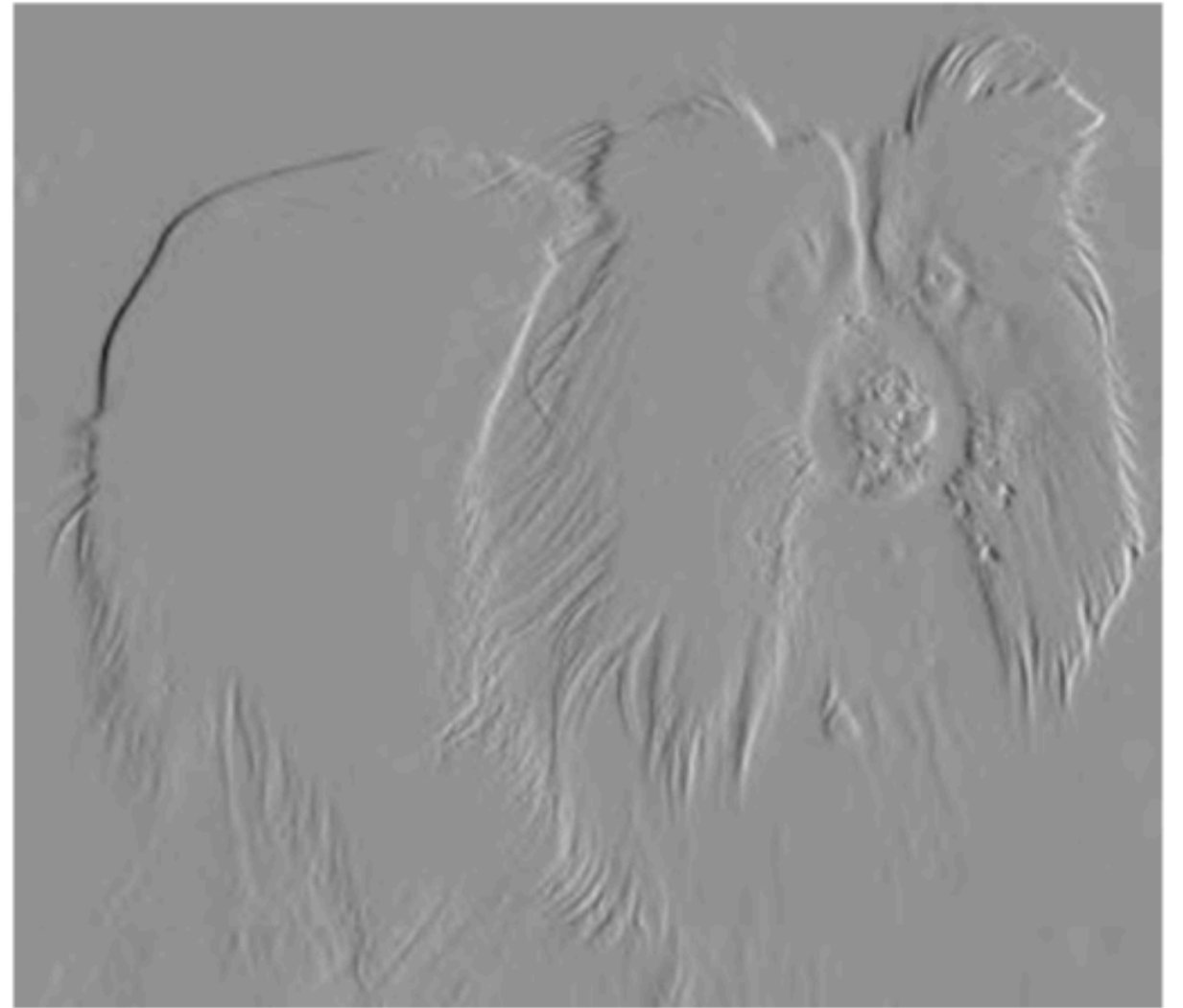


Image recognition using CNNs



Detection using only **vertically oriented edges**. Enormous efficiency improvement compared to matrix multiplication.

[Goodfellow, Bengio, Courville]

Mathematical structure

For each layer we have a **feature map**:

$$f : \mathbb{Z}^2 \rightarrow \mathbb{R}^K$$

Mathematical structure

For each layer we have a **feature map**:

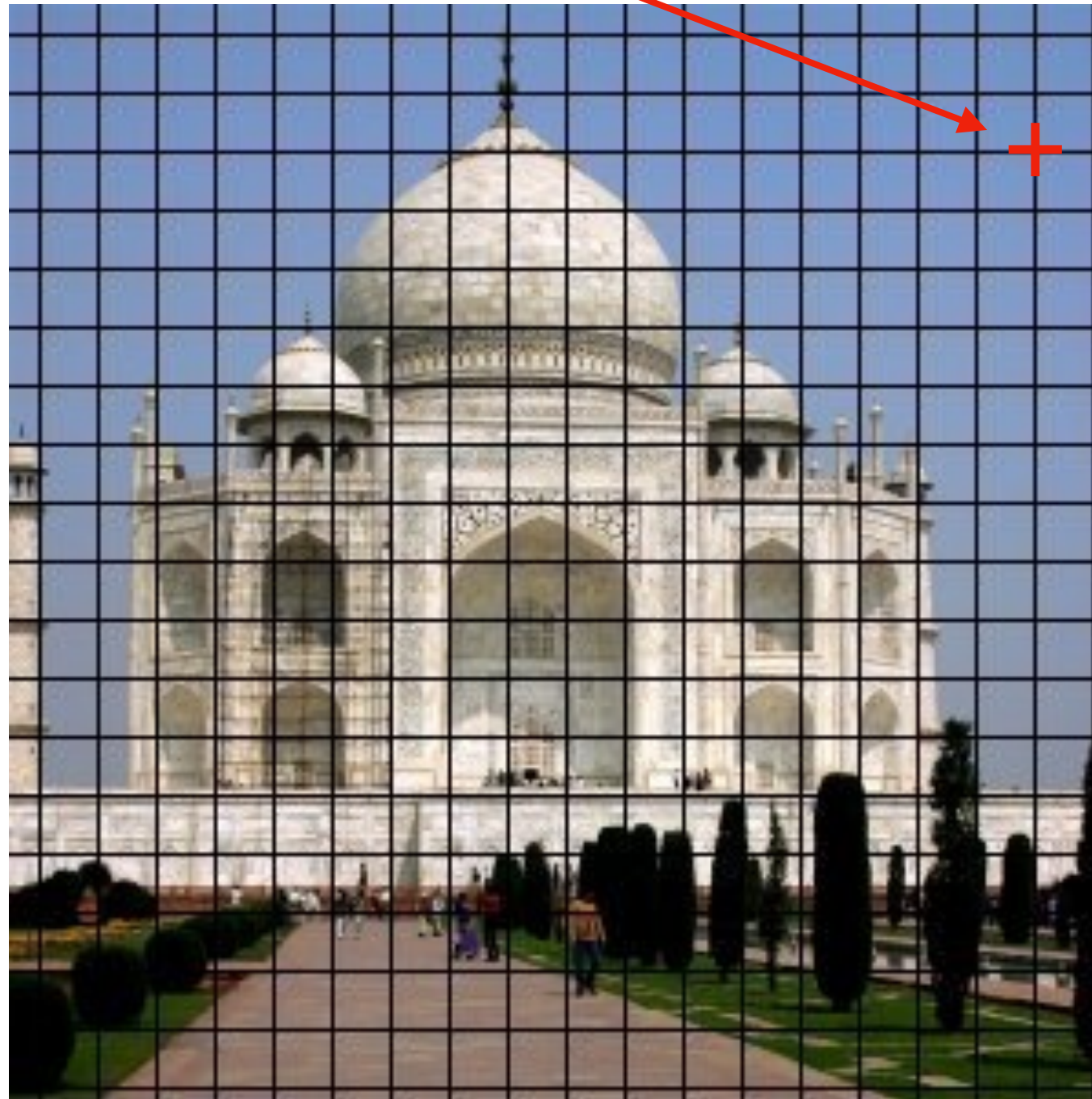
$$f : \mathbb{Z}^2 \rightarrow \mathbb{R}^{\textcircled{K}}$$

no. of channels



(p, q)

pixel coordinate

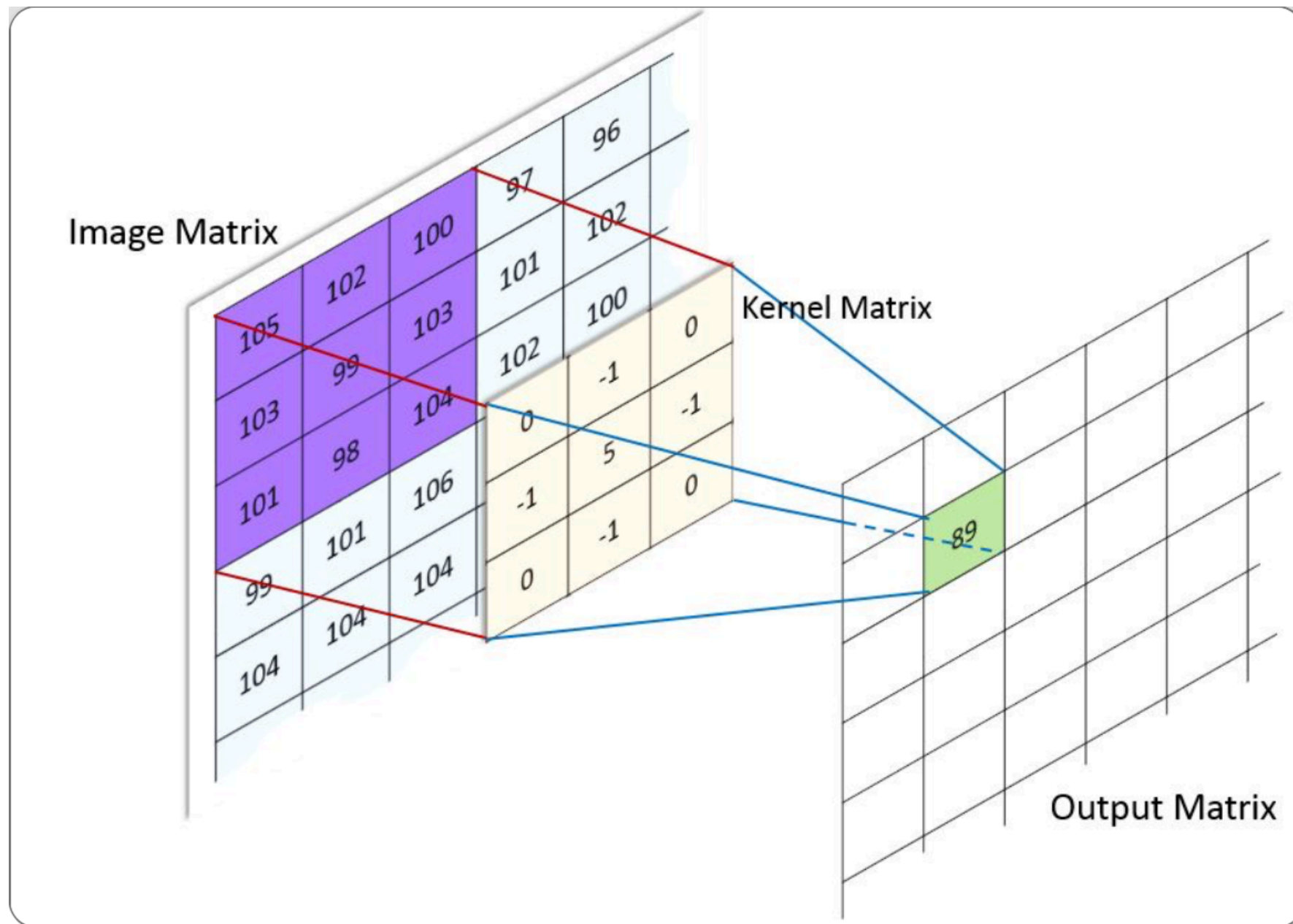


Kernel (filter): $\psi : \mathbb{Z}^2 \rightarrow \mathbb{R}^K$

Convolution:
$$[f * \psi](x) = \sum_{y \in \mathbb{Z}^2} \sum_{k=1}^K f_k(y) \psi_k(x - y)$$

Kernel (filter): $\psi : \mathbb{Z}^2 \rightarrow \mathbb{R}^K$

Convolution: $[f * \psi](x) = \sum_{y \in \mathbb{Z}^2} \sum_{k=1}^K f_k(y) \psi_k(x - y)$



Kernel (filter): $\psi : \mathbb{Z}^2 \rightarrow \mathbb{R}^K$

Convolution:
$$[f * \psi](x) = \sum_{y \in \mathbb{Z}^2} \sum_{k=1}^K f_k(y) \psi_k(x - y)$$

Translation map:
$$[T(t)f](x) = f(x + t)$$

Kernel (filter): $\psi : \mathbb{Z}^2 \rightarrow \mathbb{R}^K$

Convolution:
$$[f * \psi](x) = \sum_{y \in \mathbb{Z}^2} \sum_{k=1}^K f_k(y) \psi_k(x - y)$$

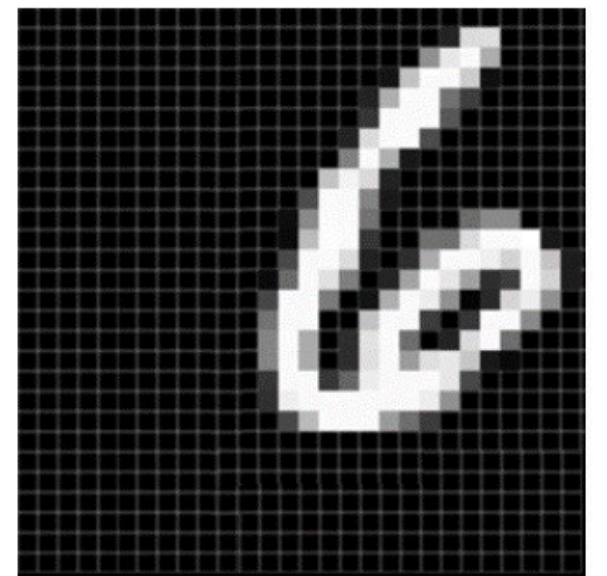
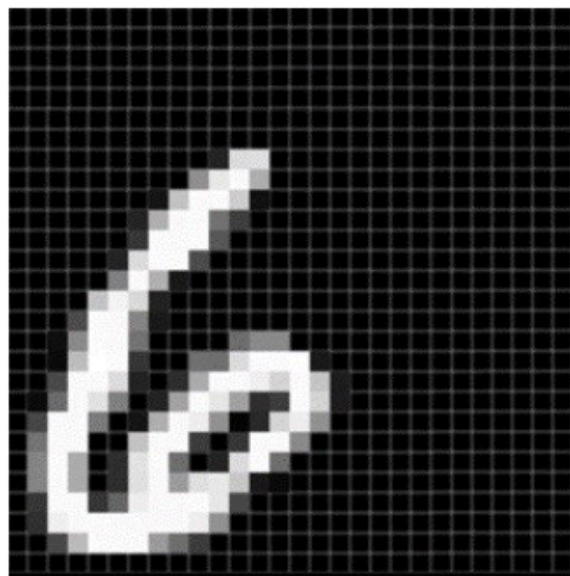
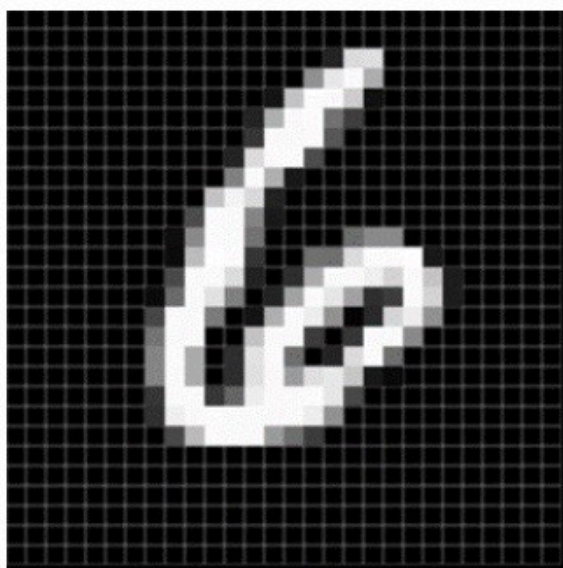
Translation map:
$$[T(t)f](x) = f(x + t)$$

Convolution is equivariant

$$[T(t)f] * \psi = T(t)[f * \psi]$$

Convolution is **equivariant**

$$[T(t)f] * \psi = T(t)[f * \psi]$$



But what about more general symmetries?

Group equivariant CNNs: General framework

G a group. $H \subset G$ subgroup.

Coset space: G/H **Vector space:** $V \cong \mathbb{R}^n$

Representation: $\rho : H \rightarrow GL(V)$

Group equivariant CNNs: General framework

G a group. $H \subset G$ subgroup.

Coset space: G/H **Vector space:** $V \cong \mathbb{R}^n$

Representation: $\rho : H \rightarrow GL(V)$

Now consider: $P = (G \times V)/H$

This is an **equivalence class** with respect to

$$(g, v) \sim (gh, \rho(h^{-1})v)$$

This is a **vector bundle**:

$$\begin{array}{ccc} V & \longrightarrow & P \\ & & \downarrow p \\ & & G/H \end{array}$$

Locally, it takes the form: $G/H \times V$

Sections of P are maps: $s : G/H \rightarrow P$ $(p \circ s = \text{Id})$

Locally, we can think of these as functions $f : G/H \rightarrow V$

Locally, we can think of these as functions $f : G/H \rightarrow V$

Example: $G = \mathbb{Z}^2$ $H = \{1\}$ $V = \mathbb{R}^K$

Feature maps are sections! $f : \mathbb{Z}^2 \rightarrow \mathbb{R}^K$

Locally, we can think of these as functions $f : G/H \rightarrow V$

Example: $G = \mathbb{Z}^2$ $H = \{1\}$ $V = \mathbb{R}^K$

Feature maps are sections! $f : \mathbb{Z}^2 \rightarrow \mathbb{R}^K$

General structure of group equivariant CNNs:

$$\left\{ \begin{array}{l} \text{Feature space of a} \\ G - \text{equivariant CNN} \end{array} \right\} \cong \left\{ \begin{array}{l} \text{Sections of vector} \\ \text{bundles } P \rightarrow G/H \end{array} \right\}$$

Layers defined with group-equivariant convolutions:

$$[f * \psi](g) = \int_G \sum_{k=1}^K f_k(h) \psi_k(gh) dh$$

$$\left\{ \begin{array}{l} \text{Feature space of a} \\ G - \text{equivariant CNN} \end{array} \right\} \cong \left\{ \begin{array}{l} \text{Sections of vector} \\ \text{bundles } P \rightarrow G/H \end{array} \right\}$$

Sections of $P \rightarrow G/H$ belong to the **induced representation**:

$$\mathcal{F} = \text{Ind}_H^G \rho = \{f : G \rightarrow V \mid f(gh) = \rho(h^{-1})f(g)\}$$

$$\left\{ \begin{array}{l} \text{Feature space of a} \\ G - \text{equivariant CNN} \end{array} \right\} \cong \left\{ \begin{array}{l} \text{Sections of vector} \\ \text{bundles } P \rightarrow G/H \end{array} \right\}$$

Sections of $P \rightarrow G/H$ belong to the **induced representation**:

$$\mathcal{F} = \text{Ind}_H^G \rho = \{f : G \rightarrow V \mid f(gh) = \rho(h^{-1})f(g)\}$$

$$\left\{ \begin{array}{l} \text{Maps between layers} \\ \text{in the CNN} \end{array} \right\} \cong \left\{ \begin{array}{l} G - \text{equivariant linear maps} \\ \text{between feature spaces } \mathcal{F} \rightarrow \mathcal{F}' \end{array} \right\}$$

$$\left\{ \begin{array}{l} \text{Feature space of a} \\ G - \text{equivariant CNN} \end{array} \right\} \cong \left\{ \begin{array}{l} \text{Sections of vector} \\ \text{bundles } P \rightarrow G/H \end{array} \right\}$$

Sections of $P \rightarrow G/H$ belong to the **induced representation**:

$$\mathcal{F} = \text{Ind}_H^G \rho = \{f : G \rightarrow V \mid f(gh) = \rho(h^{-1})f(g)\}$$

$$\left\{ \begin{array}{l} \text{Maps between layers} \\ \text{in the CNN} \end{array} \right\} \cong \left\{ \begin{array}{l} G - \text{equivariant linear maps} \\ \text{between feature spaces } \mathcal{F} \rightarrow \mathcal{F}' \end{array} \right\}$$

$$\text{Hom}_G(\mathcal{F}, \mathcal{F}')$$

(intertwining operators)

Example: Spherical signals

By Gerken, Carlsson, Linander, Ohlsson, Petersson, **D.P.**

[arXiv: 2202.03990]

$$G = SO(3)$$

$$H = SO(2)$$

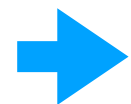
$$G/H \cong S^2$$

**Feature
maps**

$$f : S^2 \rightarrow \mathbb{R}^K$$



Relevant for :



Omnidirectional vision



Weather and climate data



Cosmology & astrophysics

$$(\kappa \star f)(R) = \int_{S^2} \kappa(R^{-1}x) f(x) \, dx$$

$$(\kappa \star f)(R) = \int_{SO(3)} \kappa(S^{-1}R) f(S) \, dS$$

Equivariance versus Augmentation for Spherical Images

JAN E. GERKEN¹, OSCAR CARLSSON¹, HAMPUS LINANDER², FREDRIK OHLSSON³,
CHRISTOFFER PETERSSON^{1,4} AND DANIEL PERSSON¹

Abstract

We analyze the role of rotational equivariance in convolutional neural networks (CNNs) applied to spherical images. We compare the performance of the group equivariant networks known as S2CNNs and standard non-equivariant CNNs trained with an increasing amount of data augmentation. The chosen architectures can be considered baseline references for the respective design paradigms. Our models are trained and evaluated on single or multiple items from the MNIST or FashionMNIST dataset projected onto the sphere. For the task of image classification, which is inherently rotationally *invariant*, we find that by considerably increasing the amount of data augmentation and the size of the networks, it is possible for the standard CNNs to reach at least the same performance as the equivariant network. In contrast, for the inherently *equivariant* task of semantic segmentation, the non-equivariant networks are consistently outperformed by the equivariant networks with significantly fewer parameters. We also analyze and compare the inference latency and training times of the different networks, enabling detailed tradeoff considerations between equivariant architectures and data augmentation for practical problems. The equivariant spherical networks used in the experiments will be made available at https://github.com/JanEGerken/sem_seg_s2cnn.

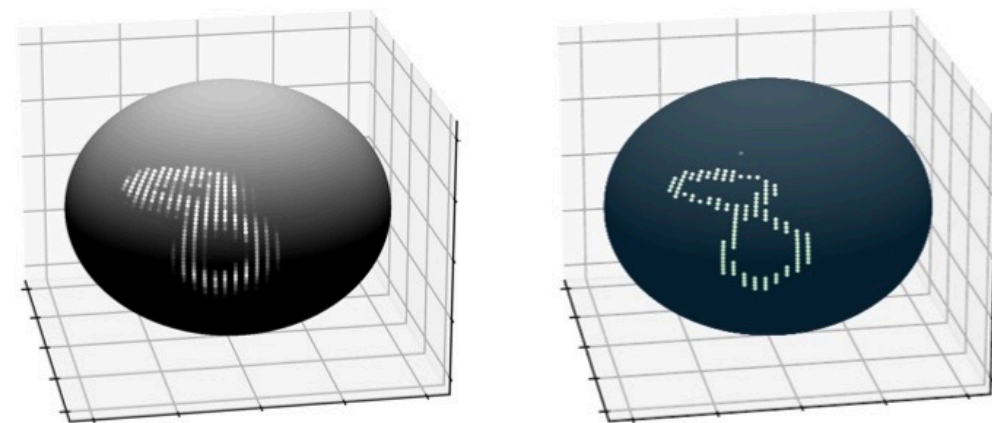


FIGURE 1.1. Sample from the spherical MNIST dataset used for semantic segmentation. Left: input data. Right: segmentation mask.

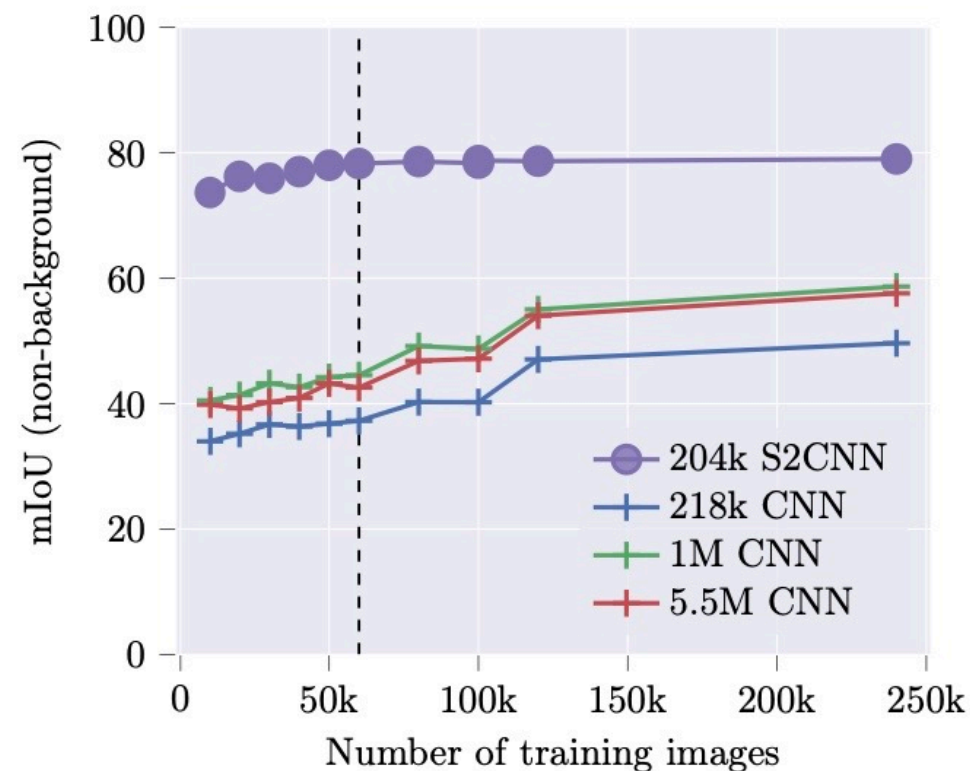
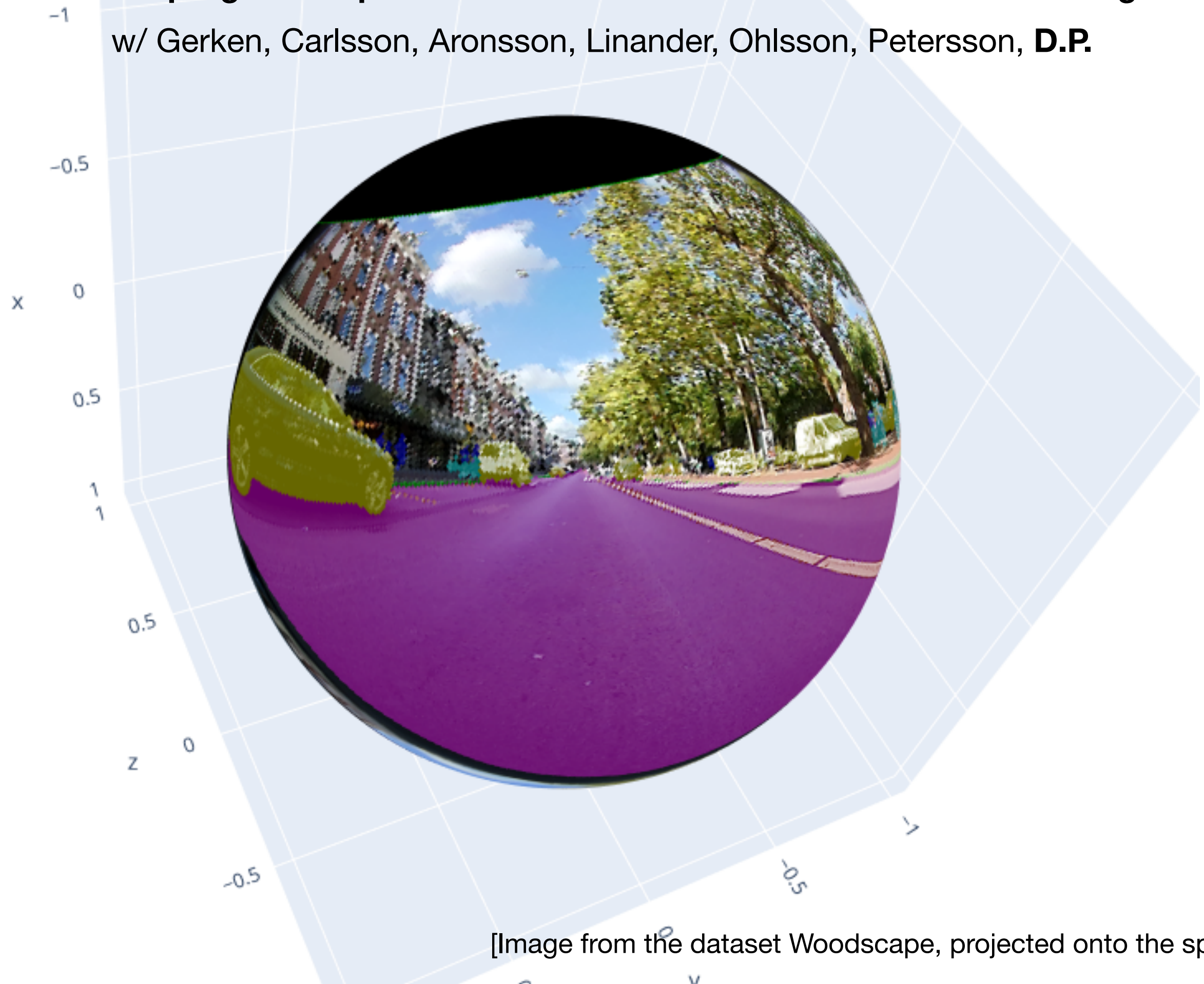


FIGURE 1.2. *Semantic Segmentation on Spherical MNIST*. The performance of the equivariant (S2CNN) and

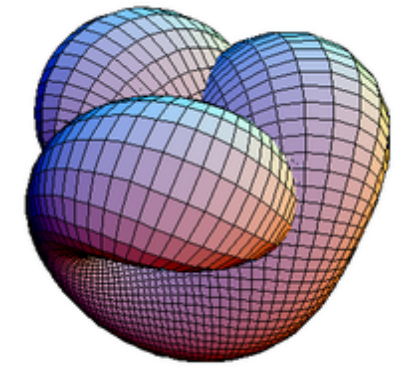
Work in progress: Equivariant neural networks for autonomous driving

w/ Gerken, Carlsson, Aronsson, Linander, Ohlsson, Petersson, **D.P.**



[Image from the dataset Woodscape, projected onto the sphere]

Gauge equivariant neural networks



[Cheng, Anagiannis, Weiler, de Haan, Cohen, Welling]

[Gerken, Carlsson, Aronsson, Linander, Ohlsson, Petersson, **D.P.**]

CNNs on arbitrary manifolds
require local equivariance

covariance w. r. t.
gauge transformations
(general coordinate transformations)

gauge equivariant
feature maps

Fields
Sections of vector bundles
(frame bundles)

“elementary feature types”
?

irreducible representations of G
elementary particles
(scalars, vectors, spinors...)

Are these the seeds of a deeper relation between neural networks and gauge theory?

Outlook

The **cross-fertilization** between deep learning, theoretical physics and mathematics is an exciting rapidly developing area of research

- ➔ Is renormalization a universal principle for deep learning?
- ➔ Relation with Quantum Information Theory?
- ➔ Can we realize a neural network as a (quantum) dynamical system?
- ➔ Relation with optimal transport theory and information geometry?
- ➔ Can we implement symmetries and conservation laws?
- ➔ A spacetime perspective of Deep Neural Networks?
- ➔ Emergent phenomena?

➡ E_{10} - equivariant neural networks?

➡ Use deep learning to calculate root multiplicities in E_{10} ?



➡ E_{10} - equivariant neural networks?

➡ Use deep learning to calculate root multiplicities in E_{10} ?

