



# Koopman Kernel Regression

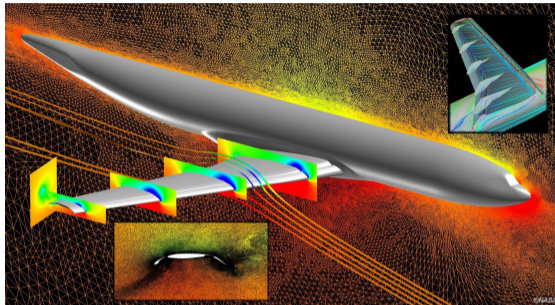
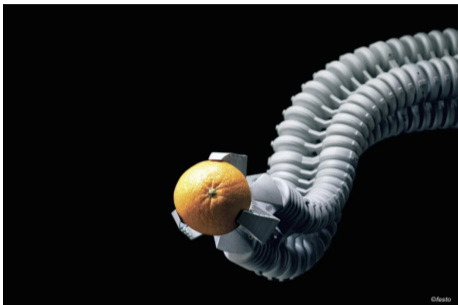
**Petar Bevanda**<sup>1</sup>   **Max Beier**<sup>1</sup>   **Armin Lederer**<sup>1</sup>   **Stefan Sosnowski**<sup>1</sup>  
**Eyke Hüllermeier**<sup>2</sup>   **Sandra Hirche**<sup>1</sup>

<sup>1</sup>Chair of Information-oriented Control  
Technical University of Munich

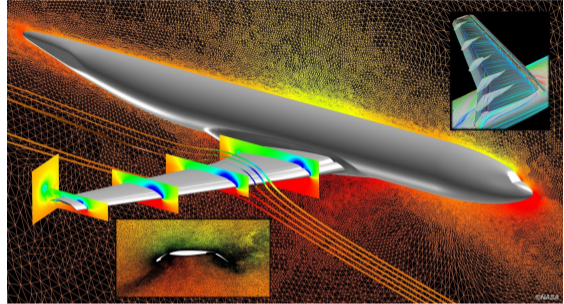
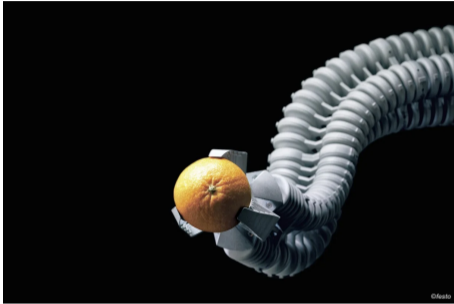
<sup>2</sup>Chair of Artificial Intelligence and Machine Learning  
Ludwig Maximilian University of Munich

37th Conference on Neural Information Processing Systems (NeurIPS 2023)

# Simple yet Expressive Representations of Complex Dynamics

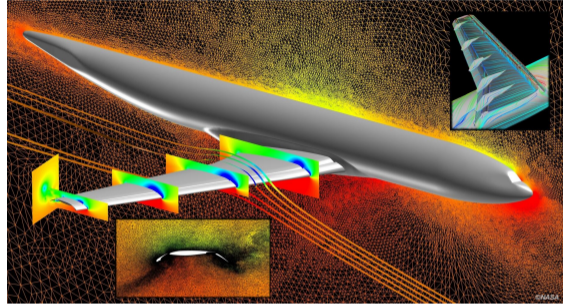
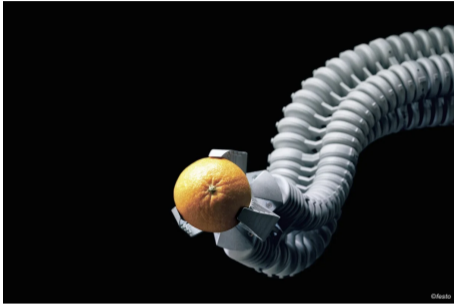


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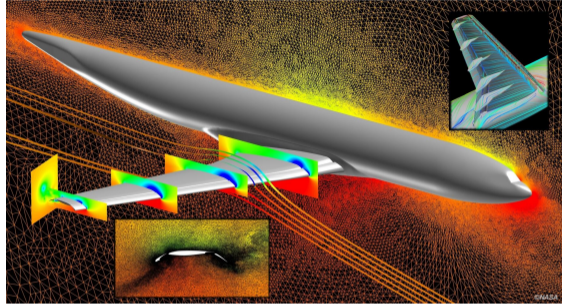
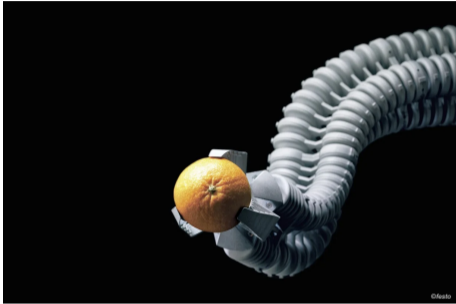
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# Simple yet Expressive Representations of Complex Dynamics



- **simple & universal representations**
- **guaranteed generalization & consistency**

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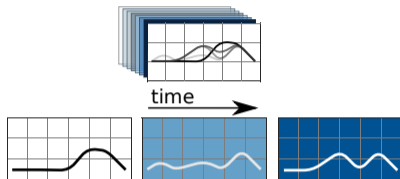


- **simple** & universal **representations**
- guaranteed **generalization** & **consistency**

⇒ *facilitating accelerated optimization-based decision making*

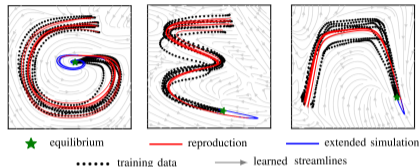
# Take the best of time-series, ODEs and RKHS

## Time-series decomposition



- discriminative ✓
- linear ✓
- time-variant ✗

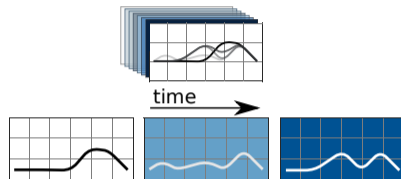
## ODEs



- generative ✓
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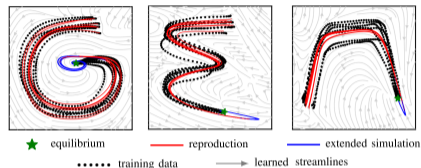
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## ODEs



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Learning in the best of both worlds?

responses  $\in \text{span}(\text{time-invariant behaviors}) \in \text{RKHS}$

# Linear & Dynamics-invariant RKHS for Learning Dynamics

## Koopmanism

Symbol  $\mathcal{K}$ : the **time-shift** or **Koopman** operator, so  $\mathcal{K}y(k) = y(k + 1)$ .



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$$\mathcal{K}^k \phi_j = \lambda_j^k \phi_j$$

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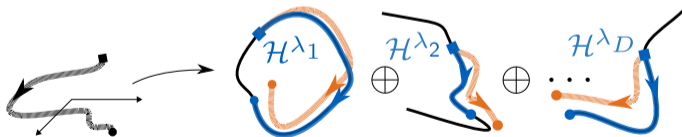
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Ours  
invariant RKHSs  $\{\mathcal{H}^{\lambda_j}\}$

Existing

[Kostic+ 2022; Klus+ 2020]



# Koopman Kernel Regression

## Koopman kernel (ridge) regression

Given  $N$  i.i.d. state-output trajectories  $\{x^{(i)}, y^{(i)}\}_{i=1}^N \in (\mathcal{X}, \mathcal{Y})^N$  of length  $H$ , compute

$$\hat{M} = \arg \min_{M \in \mathcal{S}(\mathcal{H}^{\lambda_1} \oplus \dots \oplus \mathcal{H}^{\lambda_D})} \left( \frac{1}{N} \sum_{i \in [N]} \|y^{(i)} - M(x^{(i)})\|_{\mathcal{Y}}^2 + \gamma \|M\|_{\mathcal{H}}^2 \right) \in \text{span}\{ \overset{\text{Koopman kernel}}{\downarrow} K(\cdot, x^{(i)}) \}$$

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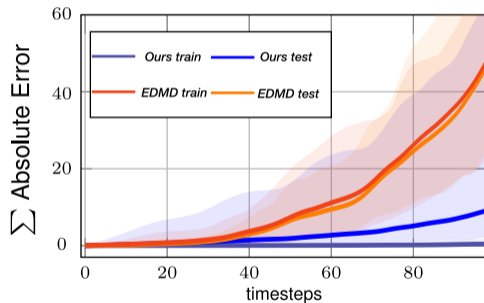
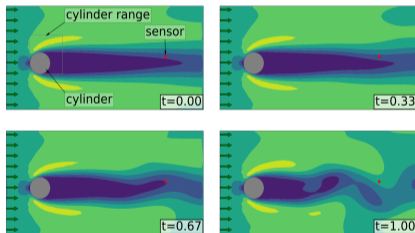
approximation error vanishing with rank  $D$

rank-independent generalization

# Practical Implications

## Flow past a cylinder

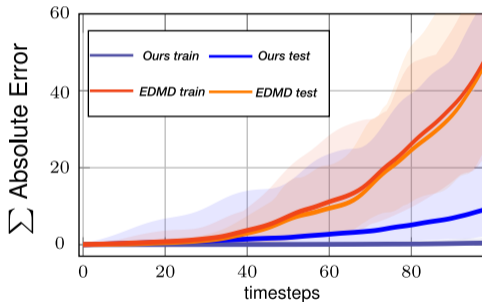
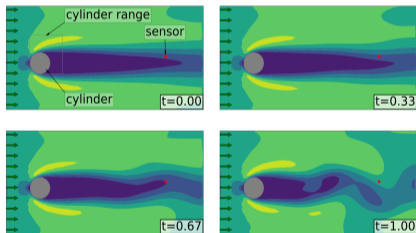
Forecasting velocity magnitude of sensor from  $50 \times 100$ -dimensional initial conditions.



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## Flow past a cylinder

Forecasting velocity magnitude of sensor from  $50 \times 100$ -dimensional initial conditions.



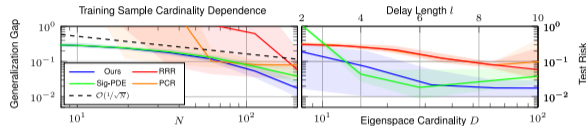
*Orders-of-magnitude* greater accuracy (also for a wide range of hyperparameters)



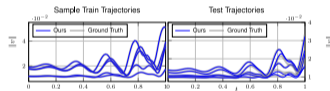
# Also in the Full Paper...

## Including but not limited to

- full theoretical results
- numerical validation
- extensive comparisons
- complexity analysis
- forecasting and training times



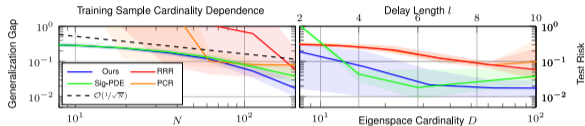
| #data = $N \times H = 200 \times 14$ | KKR           | PCR   | RRR    | Sig-PDE  |
|--------------------------------------|---------------|-------|--------|----------|
| Training [s]/Forecast [ms]           | <b>8.0/54</b> | 90/84 | 88/150 | 8.6/5900 |



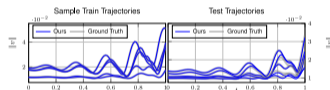
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**Spoiler:** superior to *Koopman operator regression* across the board

# References



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