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# **EDMD FOR THE KOOPMAN OPERATOR AND GENERATOR**

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## The Generator (Continued)

### Basic EDMD

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# Semigroup

The Chapman-Kolmogorov equation implies that the Koopman operators form a semigroup:

## Definition

A family of bounded linear operators  $\mathcal{T}^\tau$ ,  $\tau \geq 0$  on a Banach space  $X$  is called a **strongly continuous semigroup** if:

- (i)  $\mathcal{T}^0 = \text{Id}$ .
- (ii)  $\mathcal{T}^{\tau_1 + \tau_2} = \mathcal{T}^{\tau_1} \mathcal{T}^{\tau_2}$  for all  $0 \leq \tau_1 \leq \tau_2$ .
- (iii)  $\lim_{\tau \rightarrow 0} \mathcal{T}^\tau x = x$  for all  $x \in X$ .

# The Generator

In accordance with semigroup theory, we define:

## Definition

The generator  $\mathcal{L}$  of the semigroup of Koopman operators  $\mathcal{K}^\tau$  on  $L^2_\mu(\mathbb{X})$  acts on a function  $f$  by

$$\mathcal{L}f := \lim_{\tau \rightarrow 0} \frac{1}{\tau} (\mathcal{K}^\tau - \text{Id})f,$$

whenever this limit exists. The domain of the generator is the set of all  $f$  where the above limit exists, is denoted  $\mathcal{D}(\mathcal{L})$ .

# Generator and Time Evolution

We also know from semigroup theory that:

## Theorem

*The generator  $\mathcal{L}$  is defined on a dense subspace  $\mathcal{D}(\mathcal{L})$ . Consider the function  $v(\tau, x) = \mathcal{K}^\tau f(x)$  for  $f \in \mathcal{D}(\mathcal{L})$ . Then we have the differential equation*

$$\frac{d}{d\tau} v(\tau, x) = \mathcal{L} v(\tau, x).$$

This is the analogue of  $\dot{y} = Ly$  from last night's talk. The dynamics of the expectation value of a function in  $\mathcal{D}(\mathcal{L})$  are linear.

# The Generator of an SDE

## Proposition

*Let  $f \in C_0^\infty(\mathbb{R}^d)$  and  $X_t$  solve an SDE with drift  $b$  and diffusion  $\sigma$ . Then  $f \in \mathcal{D}(\mathcal{L})$  and the action of the generator is given by*

$$\mathcal{L}f(x) = b(x) \cdot \nabla f(x) + \frac{1}{2}a(x) : \nabla^2 f(x).$$

## Proof

### Proof.

$$\begin{aligned}\mathcal{L}f(x) &= \lim_{\tau \rightarrow 0} \frac{1}{\tau} \mathbb{E}^x(f(X_\tau) - f(X_0)) \\&= \lim_{\tau \rightarrow 0} \frac{1}{\tau} \mathbb{E}^x \left[ \int_0^\tau \nabla f^T(X_s) b(X_s) + \frac{1}{2} a(X_s) : \nabla^2 f(X_s) \, ds \right] \\&\quad + \mathbb{E}^x \left[ \int_0^\tau \nabla f^T(X_s) \sigma(X_s) \, dB_s \right] \\&= \lim_{\tau \rightarrow 0} \frac{1}{\tau} \mathbb{E}^x \left[ \int_0^\tau \nabla f^T(X_s) b(X_s) + \frac{1}{2} a(X_s) : \nabla^2 f(X_s) \, ds \right] \\&= \nabla f^T(x) b(x) + \frac{1}{2} a(x) : \nabla^2 f(x).\end{aligned}$$

# Generators and PDEs

## Corollary

Let  $f \in C_0^\infty(\mathbb{R}^d)$  and consider the function  $v(\tau, x) = \mathcal{K}^\tau f(x)$ , with  $X_\tau$  solution of an SDE. Then  $v$  solves the PDE

$$\frac{\partial}{\partial \tau} v(\tau, x) = \mathcal{L}v(\tau, x) = b(x) \cdot \nabla_x v(\tau, x) + \frac{1}{2} a(x) : \nabla_x^2 v(\tau, x).$$



## Summary

- Markovian stochastic dynamics are defined by a transition kernel.
- Time evolution of expectation values of observable functions is carried out by the semigroup of Koopman operators.
- The time evolution of these expectations is linear (in function space).
- For an SDE, this time evolution corresponds to a PDE. In particular, the "system matrix" is an unbounded differential operator.

# References

Oksendal, *Stochastic Differential Equations* (2013)

Pazy, *Semigroups of linear operators and applications to partial differential equations* (2012)

Bakry, Gentil, Ledoux, *Analysis and Geometry of Markov Diffusion Operators* (2014)



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# Galerkin Projection of the Koopman Operator: EDMD

Consider the Koopman operator  $\mathcal{K}^\tau$  on the Hilbert space  $L^2_\mu$ . Choose an  $N$ -dimensional subspace  $\mathbb{W}$  with basis  $\{\psi_i\}_{i=1}^N$  (the functions  $g$  from last night). Find a matrix  $K$ , such that, for any function  $\psi_v \in \mathbb{W}$  with coefficient vector  $v$ , we have that  $\psi_{Kv} - \mathcal{K}^\tau \psi_v$  is as small as possible. By standard best-approximation in Hilbert space, the optimal matrix representation is

$$K^\tau = G^{-1}A, \quad A_{ij} = \langle \psi_i, \mathcal{K}^\tau \psi_j \rangle_\mu, \quad G_{ij} = \langle \psi_i, \psi_j \rangle_\mu.$$

## Data-Based Approximation

If the process  $X_t$  is ergodic, i.e. time averages converge to spatial averages, we can approximate the Galerkin projection based on simulation data:

### Proposition

*Let  $\mu$  be the unique invariant measure of the process  $X_t$ . Moreover, let  $\{x_k\}_{k=1}^{\infty}$  be an infinitely long realization of the process, started from the initial distribution  $\mu$  and sampled at time step  $\tau$ . Then, with probability one*

$$G_{ij} = \langle \psi_i, \psi_j \rangle_{\mu} = \lim_{m \rightarrow \infty} \frac{1}{m} \sum_{k=1}^m \psi_i(x_k) \psi_j(x_k)$$

$$A_{ij} = \langle \psi_i, \mathcal{K}^t \psi_j \rangle_{\mu} = \lim_{m \rightarrow \infty} \frac{1}{m-1} \sum_{k=1}^{m-1} \psi_i(x_k) \psi_j(x_{k+1}).$$

Williams et al, *J. Nonlinear Sci.* (2015), Klus, Nüske, et al, *J. Nonlinear Sci.* (2018)

## Comments

- With matrices  $\Psi_X = [\psi_i(x_k)]$ ,  $\Psi_Y = [\psi_i(x_{k+1})] \in \mathbb{R}^{N \times (m-1)}$ , we basically obtain EDMD:

$$K \approx (\Psi_X \Psi_X^T)^{-1} \Psi_X \Psi_Y^T = (\Psi_X^T)^\dagger \Psi_Y^T.$$

- The lag time  $\tau$  can also equal an integer multiple of the elementary time step between data points. In this case, all pairs with time spacing  $\tau$  in between can be used ("sliding window").
- Similar results can be obtained for non-stationary systems, upon replacing a single long trajectory by many short ones.

## Example: Markov State Model

For  $k = 1, \dots, N$ , let  $S_k$  be a subset of  $\mathbb{X}$  such that  $S_k \cap S_l = \emptyset$  if  $k \neq l$ , and  $\mathbb{X} = \bigcup_{k=1}^N S_k$ . Let  $\mathbb{W} = \{\mathbf{1}_{S_k}\}_{k=1}^N$  be the subspace spanned by the indicator functions of those sets.

### Proposition

*Let  $S_k$ ,  $k = 1, \dots, N$  and  $\mathbb{W}$  as described above. Then the resulting matrix approximation  $T = G^{-1}A$  is a stochastic transition matrix of conditional transition probabilities between the discrete sets  $S_k$ . If the dynamics are reversible w.r.t. to the invariant measure  $\mu$ , then  $T$  is also a reversible transition matrix.*

Dellnitz and Junge, *SIAM J. Numer. Anal.* (1999), Schütte et al, *J. Comp. Phys.* (1999),  
Prinz et al, *J. Chem. Phys.* (2011)

