Regular Discussion 9

## 1 Bayes' Nets: Representation and Independence

Parts (a) and (b) pertain to the following Bayes' Net.

(a) Express the joint probability distribution as a product of terms representing individual conditional probabilities tables associated with the Bayes Net.
(b) Assume each node can take on 4 values. How many entries do the factors at A, D, and F have?

A: $\qquad$
D: $\qquad$
F: $\qquad$

Consider the following probability distribution tables. The joint distribution $P(A, B, C, D)$ is equal to the product of these probability distribution tables.

|  |  | A | B | $P(B \mid A)$ | B | C | $P(C \mid B)$ | C | D | $P(D \mid C)$ |
| :---: | :---: | :---: | :---: | :---: | :---: | :---: | :---: | :---: | :---: | :---: |
| A | $P(A)$ | +a | +b | 0.9 | +b | +c | 0.8 | +c | +d | 0.25 |
| +a | 0.8 | +a | -b | 0.1 | +b | -c | 0.2 | +c | -d | 0.75 |
| -a | 0.2 | -a | +b | 0.6 | -b | +c | 0.8 | -c | +d | 0.5 |
|  |  | -a | -b | 0.4 | -b | -c | 0.2 | -c | -d | 0.5 |

(c) State all non-conditional independence assumptions that are implied by the probability distribution tables.

You are building advanced safety features for cars that can warn a driver if they are falling asleep $(A)$ and also calculate the probability of a crash $(C)$ in real time. You have at your disposal 6 sensors (random variables):

- $E$ : whether the driver's eyes are open or closed
- $W$ : whether the steering wheel is being touched or not
- $L$ : whether the car is in the lane or not
- $S$ : whether the car is speeding or not
- $H$ : whether the driver's heart rate is somewhat elevated or resting
- $R$ : whether the car radar detects a close object or not
$A$ influences $\{E, W, H, L, C\} . C$ is influenced by $\{A, S, L, R\}$.
(d) Draw the Bayes Net associated with the description above by adding edges between the provided nodes where appropriate.






## 2 HMMs

Consider the following Hidden Markov Model. $O_{1}$ and $O_{2}$ are supposed to be shaded.


| $W_{1}$ | $P\left(W_{1}\right)$ |
| :---: | :---: |
| 0 | 0.3 |
| 1 | 0.7 |


| $W_{t}$ | $W_{t+1}$ | $P\left(W_{t+1} \mid W_{t}\right)$ |
| :---: | :---: | :---: |
| 0 | 0 | 0.4 |
| 0 | 1 | 0.6 |
| 1 | 0 | 0.8 |
| 1 | 1 | 0.2 |


| $W_{t}$ | $O_{t}$ | $P\left(O_{t} \mid W_{t}\right)$ |
| :---: | :---: | :---: |
| 0 | a | 0.9 |
| 0 | b | 0.1 |
| 1 | a | 0.5 |
| 1 | b | 0.5 |

Suppose that we observe $O_{1}=a$ and $O_{2}=b$.
Using the forward algorithm, compute the probability distribution $P\left(W_{2} \mid O_{1}=a, O_{2}=b\right)$ one step at a time.
(a) Compute $P\left(W_{1}, O_{1}=a\right)$.
(b) Using the previous calculation, compute $P\left(W_{2}, O_{1}=a\right)$.
(c) Using the previous calculation, compute $P\left(W_{2}, O_{1}=a, O_{2}=b\right)$.
(d) Finally, compute $P\left(W_{2} \mid O_{1}=a, O_{2}=b\right)$.

