

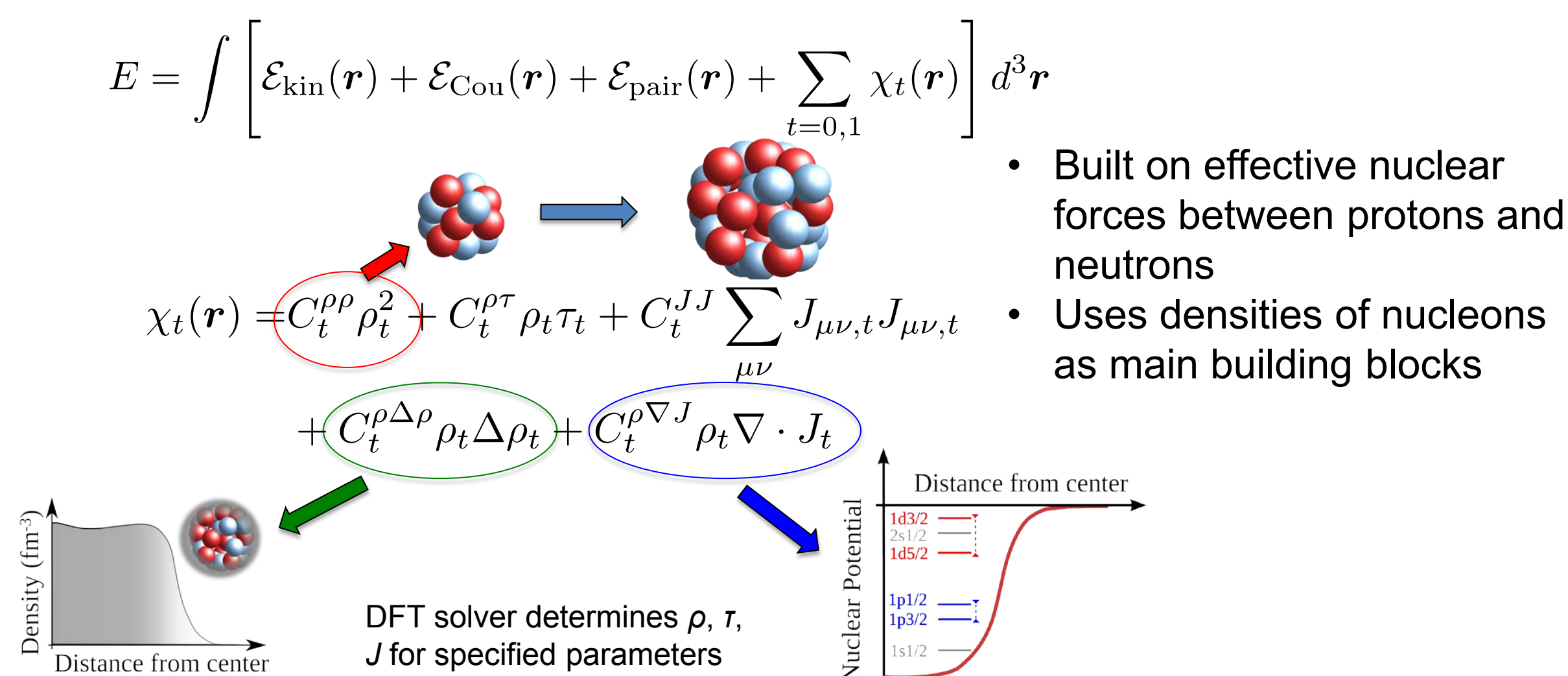
A Bayesian Approach for Parameter Estimation and Prediction using a DFT Model for Binding Energies

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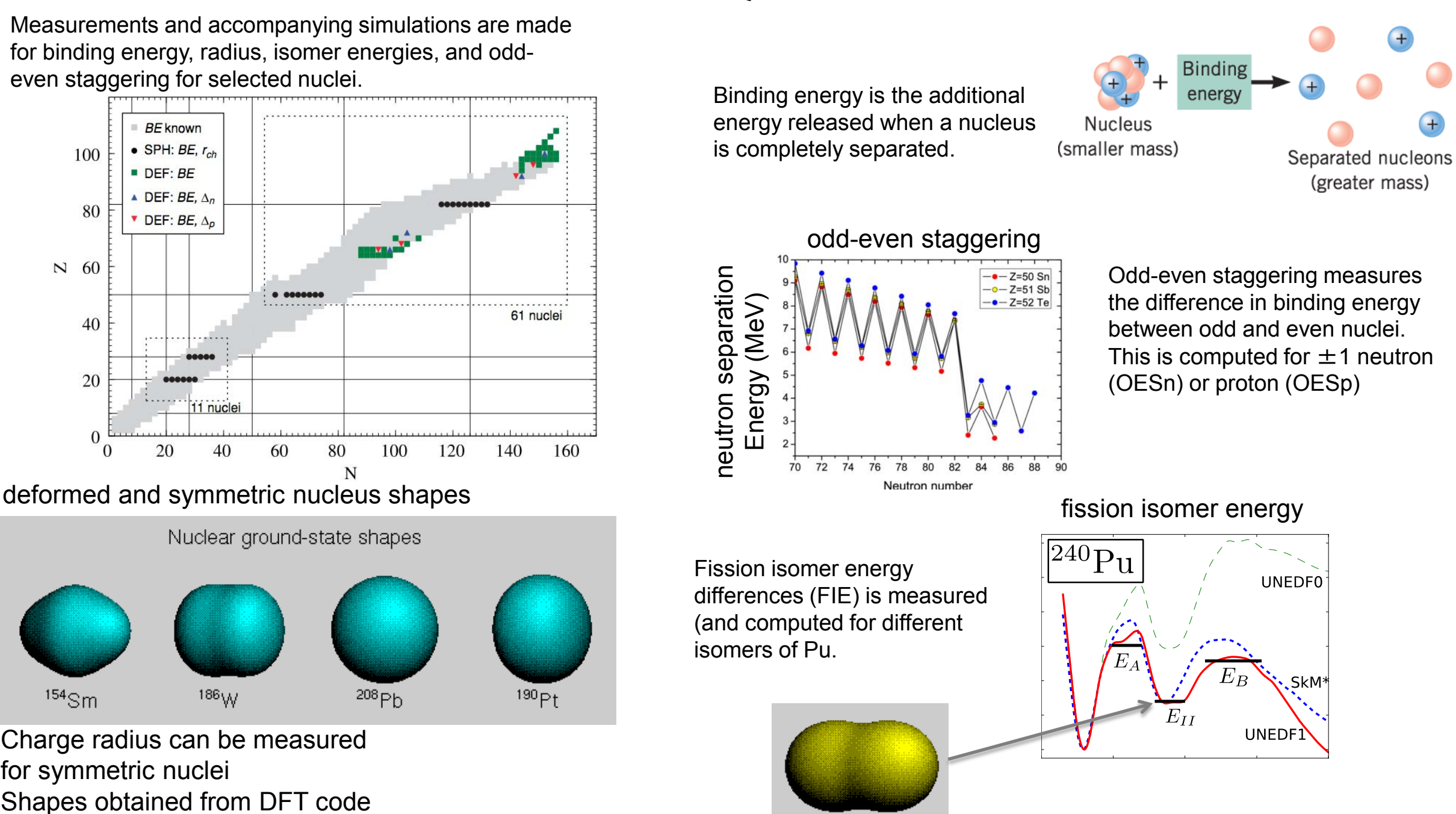
Abstract

Bayesian methods have been very successful in quantifying uncertainty in physics-based problems in parameter estimation and prediction. In these cases, physical measurements y are modeled as the best fit of a physics-based model $\eta(\theta)$, where θ denotes the uncertain, best input setting. Hence the statistical model is of the form $y = \eta(\theta) + \epsilon$, where ϵ accounts for measurement, and possibly other error sources. When non-linearity is present in $\eta(\cdot)$, the resulting posterior distribution for the unknown parameters in the Bayesian formulation is typically complex and non-standard, requiring computationally demanding approaches such as Markov chain Monte Carlo (MCMC) to produce multivariate draws from the posterior. While quite generally applicable, MCMC requires thousands, or even millions of evaluations of the physics model $\eta(\cdot)$. This is problematic if the model takes hours or days to evaluate. To overcome this computational bottleneck, we present an approach adapted from Bayesian model calibration. This approach combines output from an ensemble of computational model runs with physical measurements, within a statistical formulation, to carry out inference. A key component of this approach is a statistical response surface, or emulator, estimated from the ensemble of model runs. We demonstrate this approach with a case study in estimating parameters for a density functional theory (DFT) model, using experimental measurements from a collection of atomic nuclei. We also demonstrate how this approach produces uncertainties in predictions for recent mass measurements obtained at CARIBU Facility at Argonne National Laboratory (ANL).

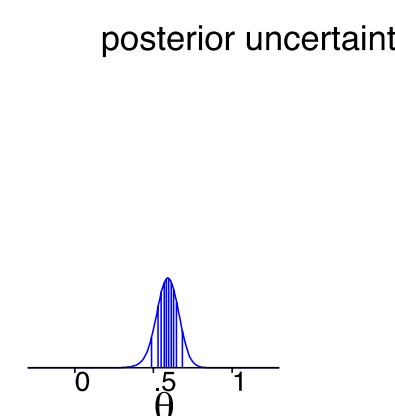
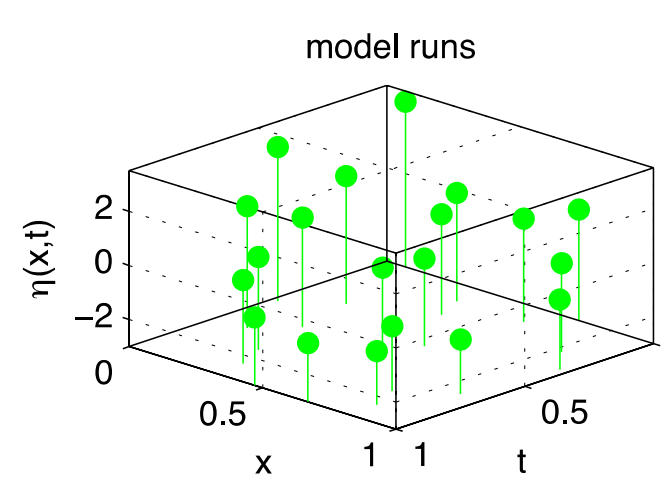
Nuclear Density Functional Theory



Measurements and Quantities of Interest



Bayesian Model Calibration Framework is Used to Combine Simulation Output and Experiments to Estimate Model Parameters and Make Predictions



Simulations and experimental observations are combined according to the Bayesian model calibration of Kennedy and O'Hagan (2001).

x model or system inputs
 θ model calibration parameters
 $\zeta(x)$ true physical system response given inputs x
 $\eta(x, \theta)$ simulator response at x and θ .
 $y(x)$ experimental observation of the physical system
 $\delta(x)$ discrepancy between $\zeta(x)$ and $\eta(x, \theta)$
 $e(x)$ may be decomposed into numerical error and bias observation error of the experimental data

$y(x) = \zeta(x) + e(x)$
 $y(x) = \eta(x, \theta) + \delta(x) + e(x)$

References:

M. Kennedy and A. O'Hagan. Bayesian calibration of computer models (with discussion). Journal of the Royal Statistical Society (Series B), 68:425–464, 2001.
D. Higdon, J. Gattiker, B. Williams, and M. Rightley. Computer Model Calibration Using High-Dimensional Output. Journal of the American Statistical Association, 103(482):570–583, 2008.
D. Higdon, J. McDonnell, N. Schunck, S. Sarich, S.M. Wild. A Bayesian approach for parameter estimation and prediction using a computationally intensive model. 2014.

Bayesian Model Formulation

$$y_{ij} = \eta(\theta, i, j) + \delta_{ij} + \epsilon_{ij}$$

misfit experimental error
$$e_{ij} = \delta_{ij} + \epsilon_{ij} \sim N(0, \lambda_i^{-1})$$

Measurement model:

$$L(y|\theta, \lambda) \propto \prod_{i,j} \lambda_i^{-1/2} \exp \left\{ -\frac{1}{2} \lambda_i (y_{ij} - \eta(\theta, i, j))^2 \right\}$$

Prior model

$$\pi(\theta) \propto I[\theta \in S]$$

$$\pi(\lambda_i) \propto \lambda_i^{a-1} e^{-b\lambda_i}$$

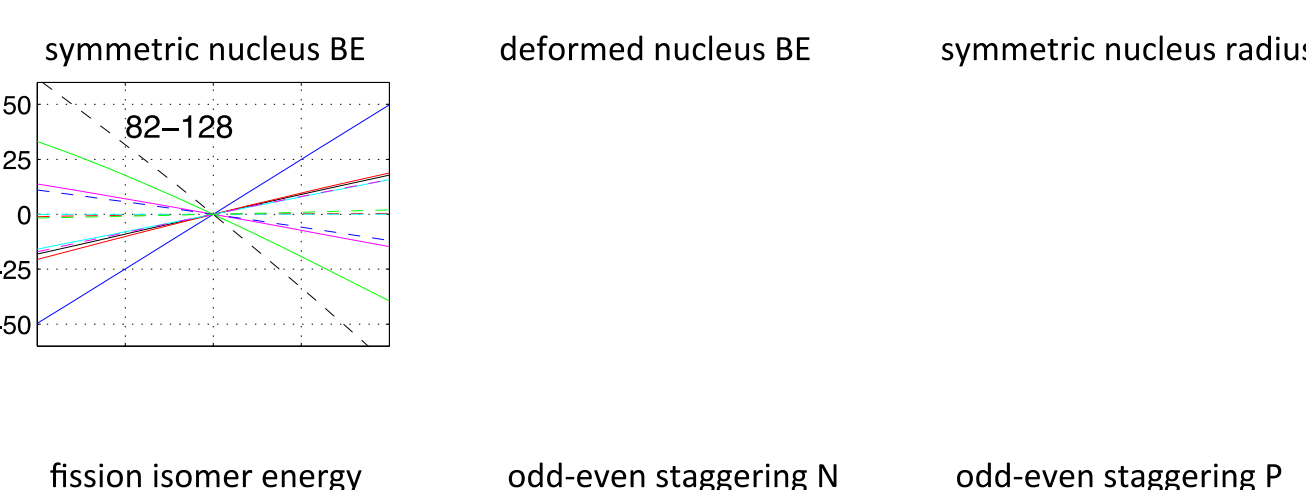
$$\eta(\cdot) \sim GP(\mu(\cdot), C_\beta(\cdot, \cdot))$$

$$\pi(\beta)$$

Posterior

$$\pi(\theta, \lambda, \eta(\cdot), \beta) \propto L(y|\theta, \lambda) \times \pi(\theta) \times \pi(\lambda) \times \pi(\eta(\cdot)) \times \pi(\beta)$$

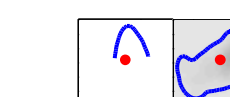
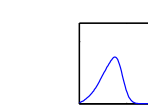
Emulating the DFT Code & Sensitivities



Estimating the response surface emulator $\eta(\cdot)$ allows exploration of the behavior of the DFT code as input parameters are varied. This figure shows the sensitivity of the masses computed via DFT as each of the 12 parameters are varied from low to high. The plots show how computed masses change for three different nuclei (Z-N) – one spherical, one deformed, and one from the new ANL measurements – as the parameters are varied, one at a time.

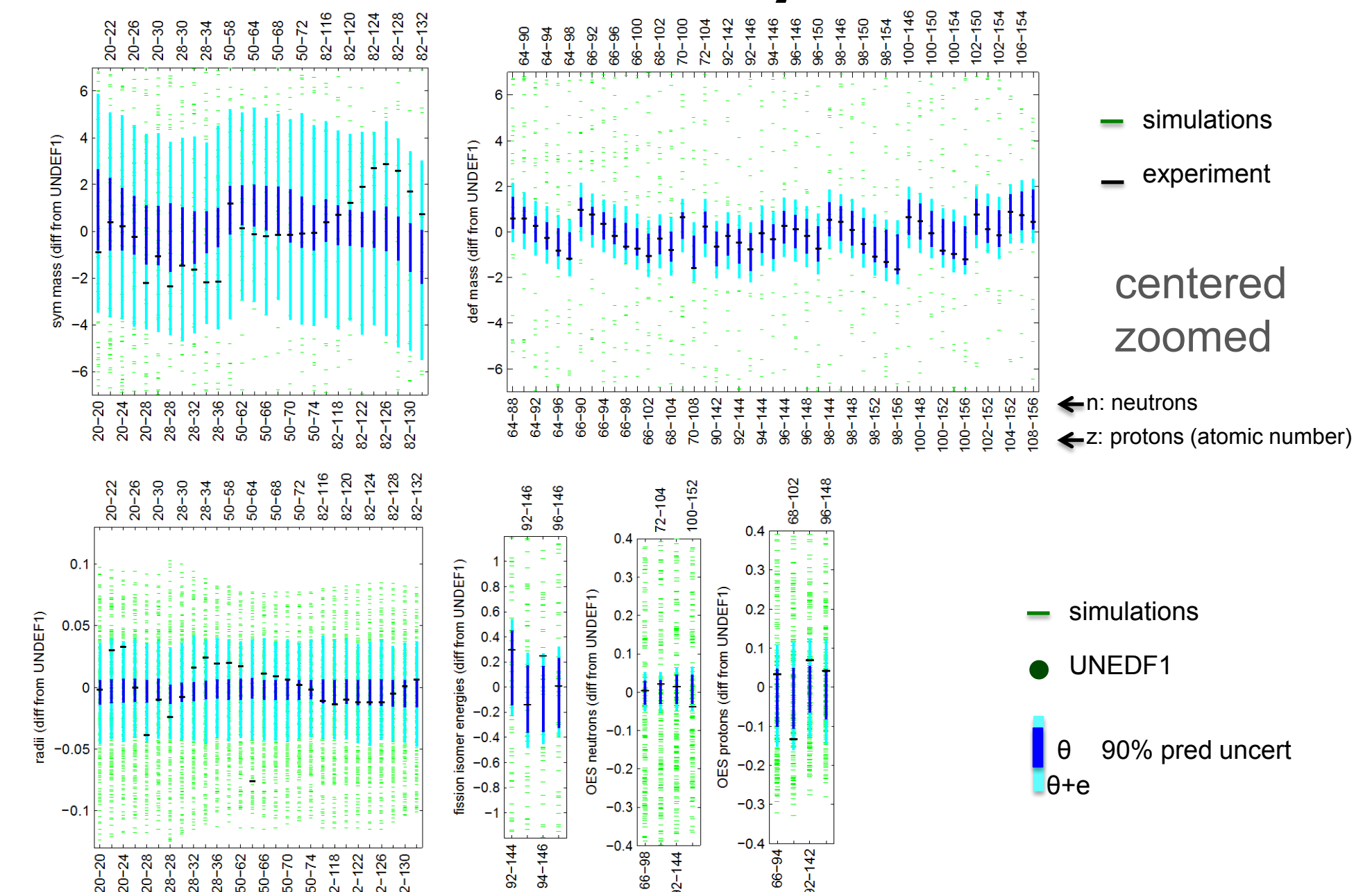
Legend for parameters: $C_0^{\rho\Delta\rho}$, $C_1^{\rho\Delta\rho}$, V_0^n , V_0^p , $C_0^{\rho\nabla J}$, $C_1^{\rho\nabla J}$, $C_0^{\rho\nabla J}$, $C_1^{\rho\nabla J}$, $1/M_s$, $1/M_p$.

Posterior Uncertainty for DFT Parameters θ

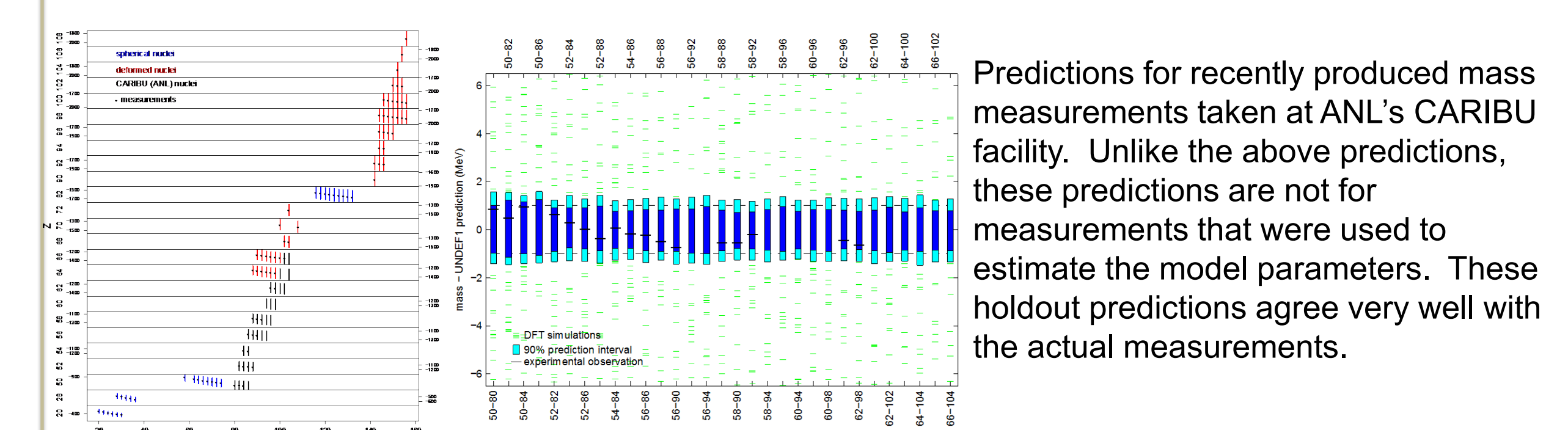


Posterior uncertainty for the 12-d DFT parameter vector after conditioning on the various data sources: masses (spherical nuclei), masses (deformed nuclei), charge radius (spherical radius), fission isomer energy, odd-even staggering (neutrons), odd-even staggering (protons). 1-d densities are shown along the diagonal of the figure; 2-d marginal distributions are represented (redundantly) along the off-diagonals.

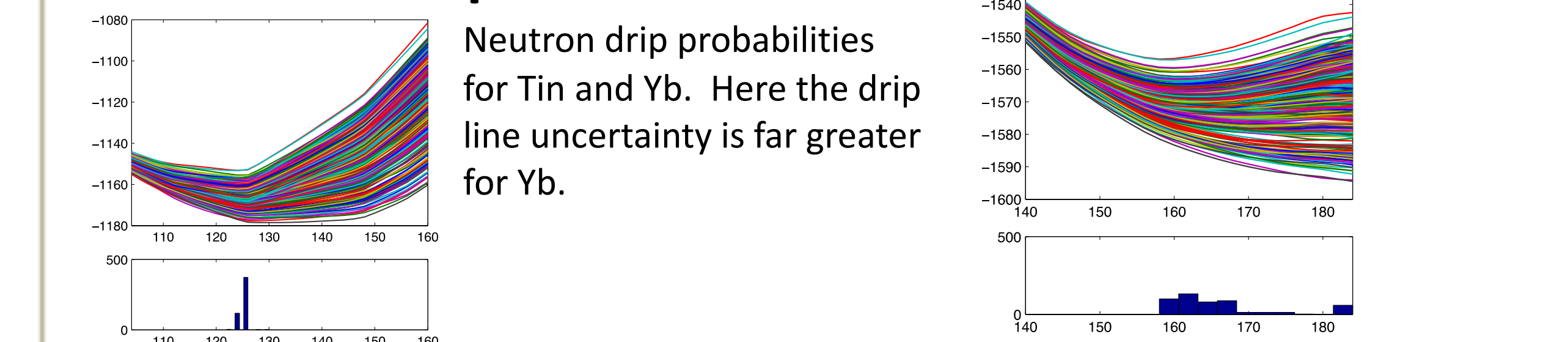
Parameter Uncertainty for Data Predictions



Posterior Predictions for new ANL N-rich Measurements



Parameter Uncertainty Propagated thru to Estimate 2-Neutron Drip Probabilities.



Drip probabilities are estimated from Monte Carlo simulations of binding energy curves for each Z.