

# Back to the Future: Logic and Machine Learning

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Logic and Machine Learning in Natural Language (LaML)  
Gothenburg, 12–13 June 2017

- ▶ Two distinct methodologies for building models of the world
  1. Logic: qualitative, symbolic and driven by domain theory
  2. ML: quantitative, numeric and driven by computational learning theory

|                 |                 |                |
|-----------------|-----------------|----------------|
| <i>tech/cov</i> | wide            | narrow         |
| deep            | <b>our goal</b> | symbolic       |
| shallow         | data-based      | <b>useless</b> |

- ▶ Discussion already mid-1990s: the rise of statistical learning methods in NLP (Gazdar, 1996; Jones et al., 2000)

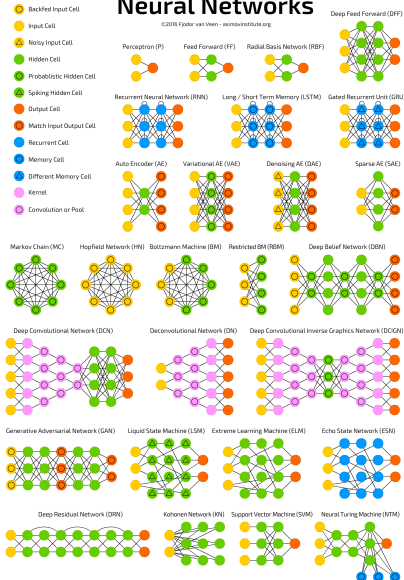
- ▶ The success of deep neural network (DNN) approaches makes the question of how these two methodologies should be used/related/integrated apposite again

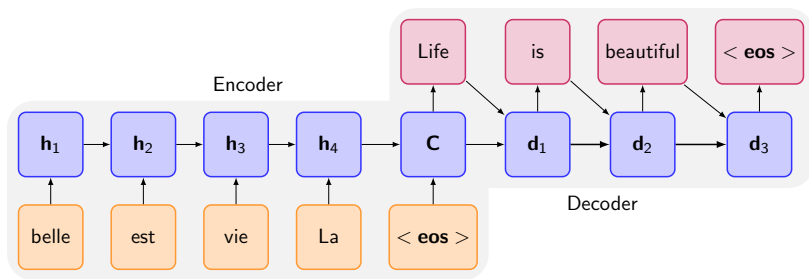
- ▶ DNNs are not unconstrained neural networks but rather that these networks have domain/task specific architectures that encode domain theoretic considerations
- ▶ DNNs can be seen as a modular learning design of composed functions



# A mostly complete chart of Neural Networks

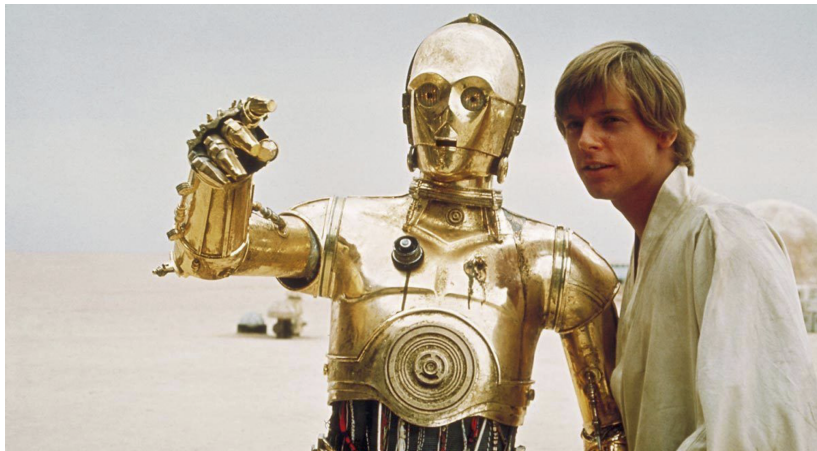
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**Figure:** Example Translation using an Encoder-Decoder Architecture

# Talking Robots

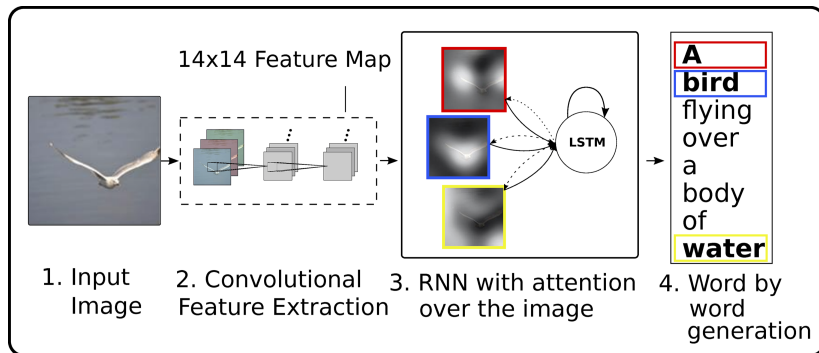


<http://www.starwars.com/databank/c-3po>

## 1. Pattern Recognition and Machine Learning Prediction (classification)

*Focus is on identifying features that have high-value states in common - a shared label in a classification setting - across a large, diverse set of training examples*

# Image Captioning



Show, Attend and Tell: Neural Image Caption Generation with Attention. Xu et al., 2015.

# Epic Fails



a woman riding a horse on a  
dirt road



an airplane is parked on the  
tarmac at an airport



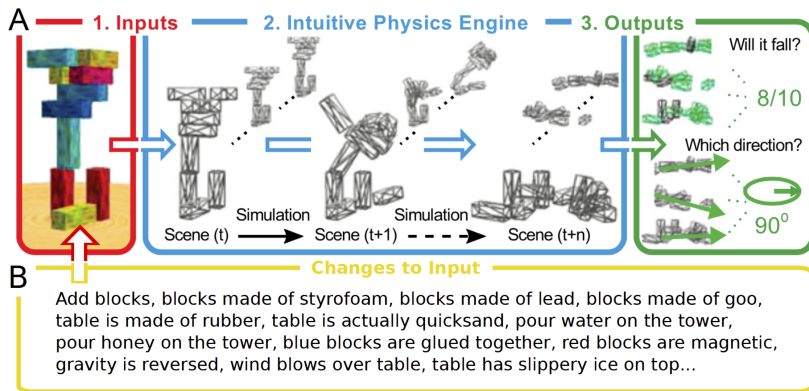
a group of people standing on  
top of a beach

Building Machines That Learn and Think Like People. Lake, B. et al.  
Behavioral and Brain Sciences (in press)

1. Pattern Recognition and Machine Learning Prediction (classification)
2. Create Mechanistic Models that are Informed by Domain Theoretic Consider

*Focus is on creating a model architecture that reflects domain theoretic considerations*

# Understanding Space: Simulation/Intuitive Physics/Imagination



Simulation as an engine of physical scene understanding. Battaglia, P. et al. Proceedings of the National Academy of Sciences, 110(45), 18327-18332

**CLASP**

centre for  
linguistic theory  
and studies in probability



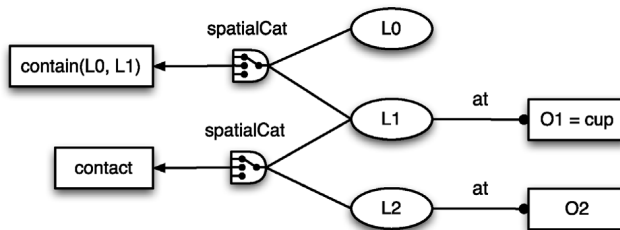


Fig. 13. The situation corresponding to, "There is a cup here. Something is touching the cup."

Semiotic schemas: A framework for grounding language in action and perception. Roy, D. Artificial Intelligence 167. Pages 170-205. 2005

- ▶ For language the mechanistic approach can be informed by logic
- ▶ Logical theories use *functions* and *compositional* operations while neural networks learn and compose functions
- ▶ Logic based domain theory of linguistic performance can inform the structural design of DNNs: model interpretability and performance.

## Perceptual domain

- ▶  $[[[34,24,48],[56,78,114]\dots]]$ : *PointMap*  
 $PointMap \sqsubseteq \text{list}(\text{list}(\text{Real}))$

## Conceptual domain

(Dobnik, 2009; Dobnik and Cooper, 2017)

## Perceptual domain

- ▶  $[[[34,24,48],[56,78,114]\dots]]$ : *PointMap*  
 $PointMap \sqsubseteq \text{list}(\text{list}(\text{Real}))$
- ▶ Object detection function  
 $(Pointmap \rightarrow \text{set} \left[ \begin{array}{ll} \text{reg} & : \text{Pointmap} \\ \text{pfun} & : (Ind \rightarrow Type) \end{array} \right] ))$   
 $\text{pfun} = \lambda x:Ind.\text{chair}(x)$

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## Perceptual domain

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$(Pointmap \rightarrow \text{set}(\left[ \begin{array}{ll} \text{reg} & : \quad Pointmap \\ \text{pfun} & : \quad (Ind \rightarrow Type) \end{array} \right] ))$

$\text{pfun} = \lambda x:Ind.\text{chair}(x)$

- ▶ Individuation function

$\lambda r: \left[ \begin{array}{ll} \text{reg}: Pointmap \\ \text{pfun}: (Ind \rightarrow Type) \end{array} \right] \cdot \left[ \begin{array}{ll} a & : \quad Ind \\ \text{loc} & : \quad \text{location}(a, r.\text{reg}) \\ c & : \quad r.\text{pfun}(a) \end{array} \right]$

## Conceptual domain

(Dobnik, 2009; Dobnik and Cooper, 2017)

# Learning to compose neural networks

Andreas et al. (2016)<sup>1</sup>

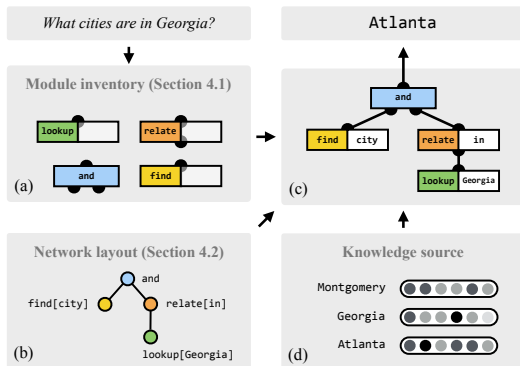


Figure 1: A learned syntactic analysis (a) is used to assemble a collection of neural modules (b) into a deep neural network (c), and applied to a world representation (d) to produce an answer.

<sup>1</sup>Thanks to Mehdi Ghanimifard for this reference.

# Learning to compose neural networks, II

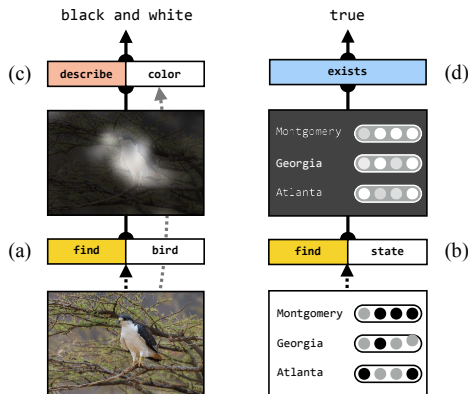


Figure 2: Simple neural module networks, corresponding to the questions What color is the bird? and Are there any states?

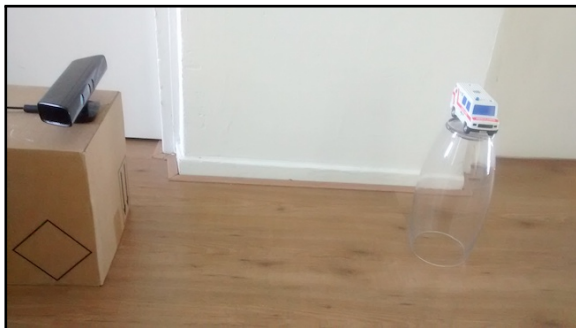
1. Pattern Recognition and Machine Learning Prediction (classification)
2. Create Mechanistic Models that are Informed by Domain Theoretic Consider
3. Learning strategies beyond presentation of data

*Focus is on optimising the learning procedure through interaction*



# Dialogue games as learning strategies

(Dobnik and de Graaf, 2017)



# Dialogue games as learning strategies



Direct instruction: objects

U: This is a cup.

S: [Object is focused on and observed.]

S: OK, I learned a cup.

# Dialogue games as learning strategies

## Direct instruction: objects

U: This is a cup.

S: [Object is focused on and observed.]

S: OK, I learned a cup.

## Direct instruction: spatial relations

U: The book is to the right of the mug.

S: [Objects are focused on and observed.]

S: OK. This relation is called “to the right of”.

S: [Objects are focused on and observed.]

U: Where are the objects?

S: The book is to the right of the mug.

# Dialogue games as learning strategies



## Reinforcement from feedback

U: What is this?

S: [Object is focused on and observed.]

S: This is a cup.

U: That is correct.

S: [Observation is added to the models.]

# Dialogue games as learning strategies

## Reinforcement from feedback

U: What is this?

S: [Object is focused on and observed.]

S: This is a cup.

U: That is correct.

S: [Observation is added to the models.]

## Self-initiative: spatial relations

S: [Objects are focused on and observed.]

S: One of the objects is book, the other one is box. Please tell me where things are.

U: The book is to the left of the box.

S: OK, this relation is called “to the left of”.

## Results over 4 rounds: direct instruction only

| →        | apple       | banana      | bear        | book        | cap  | car         | cup         | paint       | shoe        | shoe-box    | C-NI  |
|----------|-------------|-------------|-------------|-------------|------|-------------|-------------|-------------|-------------|-------------|-------|
| apple    | <b>.343</b> | .227        | .076        | .046        | .099 | .058        | .126        | .074        | .053        | .166        | .116  |
| banana   | .201        | <b>.357</b> | .058        | .035        | .085 | .087        | .148        | .066        | .046        | .124        | .155  |
| bear     | .080        | .121        | <b>.260</b> | .074        | .089 | .091        | .120        | .099        | .074        | .136        | .123  |
| book     | .142        | .233        | .074        | <b>.496</b> | .114 | .197        | .246        | .130        | .085        | .220        | .250  |
| cap      | .122        | <b>.208</b> | .076        | .049        | .146 | .096        | .103        | .083        | .061        | .114        | -.062 |
| car      | .104        | .183        | .053        | .067        | .077 | <b>.414</b> | .119        | .076        | .069        | .149        | .231  |
| cup      | .099        | .145        | .063        | .066        | .091 | .052        | <b>.330</b> | .094        | .054        | .120        | .185  |
| paint    | .119        | .140        | .075        | .076        | .083 | .147        | .121        | <b>.221</b> | .062        | .111        | .075  |
| shoe     | .078        | .123        | .070        | .056        | .079 | .116        | .124        | .076        | <b>.319</b> | .103        | .196  |
| shoe-box | .190        | .332        | .099        | .188        | .145 | .305        | .313        | .166        | .111        | <b>.376</b> | .044  |

## Results over 4 rounds: direct instruction only

| →        | apple       | banana      | bear        | book        | cap  | car         | cup         | paint       | shoe        | shoe-box    | C-NI  |
|----------|-------------|-------------|-------------|-------------|------|-------------|-------------|-------------|-------------|-------------|-------|
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| paint    | .119        | .140        | .075        | .076        | .083 | .147        | .121        | <b>.221</b> | .062        | .111        | .075  |
| shoe     | .078        | .123        | .070        | .056        | .079 | .116        | .124        | .076        | <b>.319</b> | .103        | .196  |
| shoe-box | .190        | .332        | .099        | .188        | .145 | .305        | .313        | .166        | .111        | <b>.376</b> | .044  |

C-NI ranking: book > car > shoe > cup > banana > bear >  
apple > paint > shoe-box > cap

16 locations around the landmark tested randomly twice: direct instruction only

| Match            | Evaluator 1 |        | Evaluator 2 |        | Evaluator 1 + 2 |        |
|------------------|-------------|--------|-------------|--------|-----------------|--------|
| Independent      | 8           | 0.25   | 7           | 0.2188 | 15              | 0.2344 |
| Secondary        | 11          | 0.3438 | 13          | 0.4063 | 24              | 0.375  |
| Indep. + Second. | 19          | 0.5938 | 20          | 0.6251 | 39              | 0.6094 |
| Incorrect        | 13          | 0.4063 | 12          | 0.375  | 25              | 0.3906 |
| Total            | 32          | 1      | 32          | 1      | 64              | 1      |



# Spatial relations: confusion matrix

When some contextual parameters are missing

|        | behind   | front    | left     | right    | close    | near     | Total |
|--------|----------|----------|----------|----------|----------|----------|-------|
| behind | <b>4</b> | 2        | 1        | 0        | 0        | 2        | 9     |
| front  | 0        | <b>5</b> | 3        | 3        | 6        | 0        | 17    |
| left   | 0        | 6        | <b>1</b> | 0        | 0        | 0        | 7     |
| right  | 4        | 1        | 3        | <b>3</b> | 0        | 1        | 12    |
| close  | 1        | 9        | 1        | 0        | <b>1</b> | 2        | 14    |
| near   | 1        | 1        | 1        | 0        | 1        | <b>1</b> | 5     |
| Total  | 10       | 24       | 10       | 6        | 8        | 6        | 64    |

# Spatial relations: confusion matrix

When some contextual parameters are missing

|        | behind   | front    | left     | right    | close    | near     | Total |
|--------|----------|----------|----------|----------|----------|----------|-------|
| behind | <b>4</b> | 2        | 1        | 0        | 0        | 2        | 9     |
| front  | 0        | <b>5</b> | 3        | 3        | 6        | 0        | 17    |
| left   | 0        | 6        | <b>1</b> | 0        | 0        | 0        | 7     |
| right  | 4        | 1        | 3        | <b>3</b> | 0        | 1        | 12    |
| close  | 1        | 9        | 1        | 0        | <b>1</b> | 2        | 14    |
| near   | 1        | 1        | 1        | 0        | 1        | <b>1</b> | 5     |
| Total  | 10       | 24       | 10       | 6        | 8        | 6        | 64    |

- ▶  $A_o = 0.2344, \kappa = 0.0537$
- ▶ Appropriate alternatives:
  - ▶ topological - projective: “left” as “front”, “close” as “front”
  - ▶ FOR variation: “right” as “left”

- ▶ Simply applying a powerful learning algorithm to a large dataset (pattern recognition) is problematic if the focus is solely on ML tasks rather than on domain theoretic considerations.



Yoav Goldberg

Follow

Senior Lecturer at Bar Ilan University. Working on NLP. Recently with Neural Nets. Published a book ...

Jun 9 · 14 min read

## An Adversarial Review of “Adversarial Generation of Natural Language”

**Or, for fucks sake, DL people, leave language alone and stop saying you solve it.**

[edit: some people commented that they don't like the us-vs-them tone and that “deep learning people” can—and some indeed do—do good NLP work. To be clear: I fully agree. #NotAllDeepLearners ]

[**update:** I added some clarifications based on responses to this piece. I suggest reading them after reading this one. ]

[**update:** Yann LeCun responded on facebook, followed by my response to Yann's]

- ▶ However, DNNs have modular architectures that can be specifically tailored or structured to the needs of a specific domain or task
- ▶ Introduce domain relevant structural constraints into the model via the network architecture
  - ▶ Early examples: (Feldman et al., 1988; Feldman, 1989; Regier, 1996)
  - ▶ The example of Johnson et al. in Marco's earlier talk fits within our understanding of this approach.

- ▶ Relating and understanding the modular design of DNNs to models of language and cognition provides an interesting research question for the future.
  - ▶ Pattern recognition
  - ▶ Mechanistic architectures
  - ▶ Learning is through interaction

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*Accepted for Journal of Language Modelling* *n*(*n*), 1–27.

- Dobnik, S. and E. de Graaf (2017, 22–24 May). KILLE: a framework for situated agents for learning language through interaction. In J. Tiedemann (Ed.), *Proceedings of the 21st Nordic Conference on Computational Linguistics (NoDaLiDa)*, Volume 131 of *Linköping Electronic Conference Proceedings and NEALT Proceedings Series Vol. 29*, Gothenburg, Sweden, pp. 1–10. Northern European Association for Language Technology (NEALT): Linköping University Electronic Press.
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