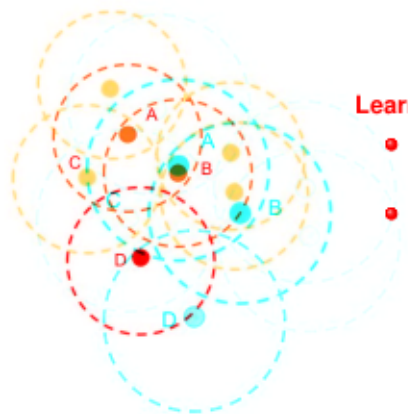


Interpretable Machine Learning

Increasing Trust in Explanations

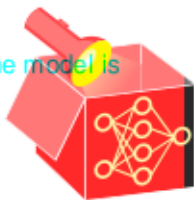


Learning goals

- Understand the aspects that undermine users' trust in an explanation
 - Understand the aspects that undermine users' trust in an explanation
- Learn diagnostic tools that could increase trust
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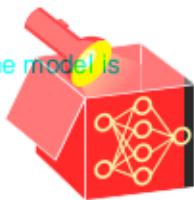
MOTIVATION & IMPORTANT PROPERTIES

- Local explanations should not only make a model interpretable but also reveal if the model is trustworthy



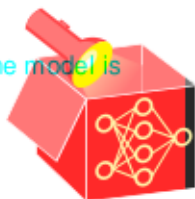
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- Interpretable** "Why did the model come up with this decision?"

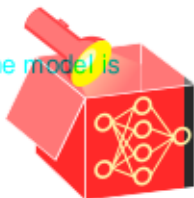


MOTIVATION & IMPORTANT PROPERTIES

- Local explanations should not only make a model interpretable but also reveal if the model is trustworthy
- **Interpretable**: "Why did the model come up with this decision?"
- **Trustworthy**: "How certain is this explanation?"
 - accurate insights into the inner workings of our model
 - Failure case: generation is based on inputs in areas where the model was trained with little or no training data (extrapolation)

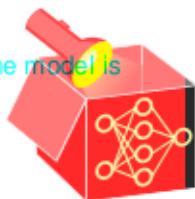


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 - 2 robust (i.e. low variance)
 - Expectation: similar explanations for similar data points with similar predictions
 - multiple sources of uncertainty exist
 - However, multiple sources of uncertainty exist
- ↪ measure how robust an IML method is to small changes in the input
- ↪ data or parameters out-of-distribution?
- ↪ Is an observation out-of-distribution?

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 - However, multiple sources of uncertainty exist
 - small changes in the input data or parameters
 - measure how robust an IML method is to small changes in the input data or parameters
 - out-of-distribution?
 - Is an observation out-of-distribution?
- Failing in one of these ~> undermining users' trust in the explanations
- Failing in one of these ~> undermining users' trust in the explanations
~> undermining trust in the model

OUT-OF-DISTRIBUTION DETECTION

- Models are unreliable in areas with little data support
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 - ↪ explanations from local explanation methods are unreliable
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 - The data for LIME's surrogate model
 - Counterfactuals themselves
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- Two very simple and intuitive approaches
 - Classifier for out-of-distribution
 - Clustering
- More complicated also possible, e.g., variational autoencoders [Daxberger et al. 2020]
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OUT-OF-DISTRIBUTION DETECTION: OOD-CLASSIFIER



- Problem: we have only in-distribution data
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- Idea: Hallucinate new (out-of-distribution) data by randomly sample data points
- Learn a binary classifier to distinguish between the origins of the data

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- Problem: we have only in-distribution data
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- Idea: Hallucinate new (out-of-distribution) data by randomly sample data points
- Learn a binary classifier to distinguish between the origins of the data
- Study whether an explanation approach can be fooled • Dylan Sack et al. 2020
- Study whether an explanation approach can be fooled by an unbiased model for all out-of-distribution samples • Dylan Sack et al. 2020
 - Hide bias in the true (deployed) model, but use an unbiased model for all out-of-distribution samples
- Important way to diagnose an explanation approach
- Important way to diagnose an explanation approach

OUT-OF-DISTRIBUTION DETECTION: CLUSTERING VIA DBSCAN

- DBSCAN is a data clustering algorithm (Martin Ester et al. 1996)
- DBSCAN is a data clustering algorithm (Applications with Noise)
(Density-Based Spatial Clustering of Applications with Noise)



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- DBSCAN is a data clustering algorithm (Applications with Noise)
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- For this method, we define an ϵ -neighborhood:

Given a dataset $X = \{\mathbf{x}^{(i)}\}_{i=1}^n$, an ϵ -neighborhood for $\mathbf{x} \in \mathcal{X}$ is defined as

$$\mathcal{N}_\epsilon(\mathbf{x}) = \{\mathbf{x}^{(i)} \in \mathcal{X} \mid d(\mathbf{x}, \mathbf{x}^{(i)}) \leq \epsilon\}.$$

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• Border points form an own cluster with all its neighborhood points

• Border points within $\mathcal{N}_\epsilon(\mathbf{x})$

• Part of a cluster defined by a core point

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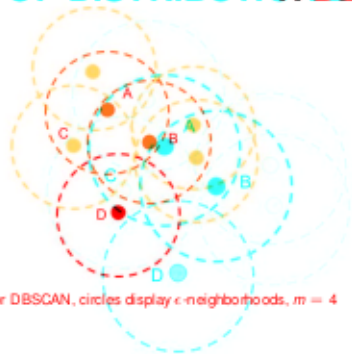
• Noise points Part of a cluster defined by a core point

• Noise points Are not within $\mathcal{N}_\epsilon(\mathbf{x})$

• Not part of any cluster

• Not part of any cluster

OUT-OF-DISTRIBUTION DETECTION



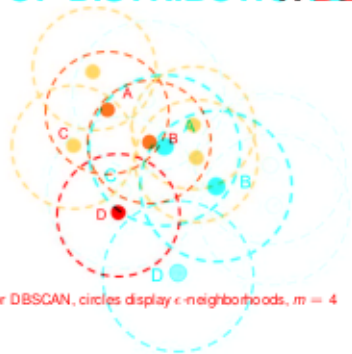
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- Green points A and B are core points and form one cluster since they lie in each others neighborhood; all yellow points are border points of this cluster
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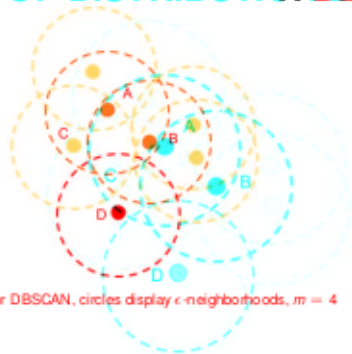
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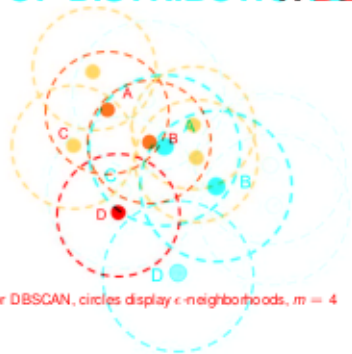
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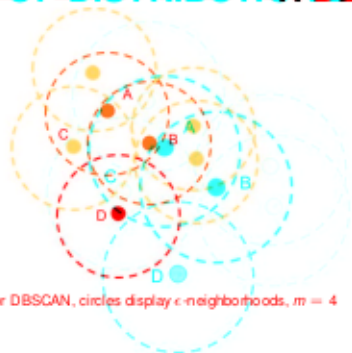
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 - Depending on the distance metric $d(\cdot)$, DBSCAN could suffer from the “curse of dimensionality”
 - The choice of ϵ and m is not clear a-priori
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 - Since D is not part of the neighborhood of core points, it is a noise point
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- Objective: Similar explanations for similar inputs (in a neighborhood)



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Alvarez-Melis and Jaakkola 2018:

An explanation method $g: \mathcal{X} \rightarrow \mathbb{R}^m$ is locally Lipschitz if

- for every $x_0 \in \mathcal{X}$ there exist $\delta > 0$ and $\omega \in \mathbb{R}$
- such that $\|x - x_0\| < \delta$ implies $\|g(x) - g(x_0)\| \leq \omega \|x - x_0\|$

Note that, for LIME, g returns the m coefficients of the surrogate model



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- ω is rarely known a-priori but it could be estimated as follows:

$$\hat{\omega}_{\mathbf{x}}(\mathbf{x}) \in \arg \max_{\mathcal{N}_{\epsilon}(\mathbf{x})} \frac{\|g(\mathbf{x}) - g(\mathbf{x}^{(i)})\|_2}{d(\mathbf{x}, \mathbf{x}^{(i)})},$$

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