On the Algorithmic Power of Spiking Neural Networks

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• Mathematical models for "biological neural networks".

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Neurons: Nerve cells

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Synapses: Connections between neurons

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Neurons: Nerve cells

Synapses: Connections between neurons

Spikes: Instantaneous signals

• Mathematical models for "biological neural networks".



Neurons Synapses Spikes

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- Various models since the 1900s.
 - Integrate-and-fire [Lap07], Hodgkin-Huxley [HH52], their variants [Fit61, Ste65, ML81, HR84, Ger95, KGH97, BL03, FTHVVB03, I+03, TMS14].



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SNNs seem to have non-trivial computational power. Can we understand them better through the lens of algorithms?



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External charging



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Spiking effects



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Firing Rule $s_i(t) = 1 \Leftrightarrow u_i(t) \ge \eta$



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• Firing rate: x(t) = (# spikes before time t)/t

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$$\begin{array}{c} \overset{0.2}{1} \\ t = 1000 \end{array} \qquad \begin{array}{c} \overset{0.2}{1} \\ \overset{0}{1} \\ \overset{0}{1}$$

[Barrett-Denève-Machens, NIPS 2013]

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Using an "optimization problem" to analyze the firing rate of an integrate-and-fire SNN.



(**C**,**I**)

firing rate

[Barrett-Denève-Machens, NIPS 2013]



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The first proof for the firing rate of integrate-and-fire SNNs efficiently solving the non-negative least squares problem.

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• Further show that the firing rate of integrate-and-fire SNN efficiently finds the sparse solution (in the ℓ_1 sense)

The first proof for the firing rate of integrate-and-fire SNNs efficiently solving the non-negative least squares problem.

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What if there are infinitely many solutions?

• Further show that the firing rate of integrate-and-fire SNN efficiently finds the sparse solution (in the ℓ_1 sense), by implementing a primal-dual + projected gradient descent algorithm.

Given
$$A \in \mathbb{R}^{m \times n}$$
, $b \in \mathbb{R}^{m}$, and $\epsilon > 0$. Suppose A satisfies some *regular* conditions. Set $C = \begin{pmatrix} A^{\top}A & -A^{\top}A \\ -A^{\top}A & A^{\top}A \end{pmatrix}$, $I = \begin{pmatrix} A^{\top}b \\ -A^{\top}b \end{pmatrix}$, and properly set the integrate-and-fire SNN.

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integrate-and-fire SNN. Let x^* be the optimal solution to the ℓ_1
minimization problem.

$$\min_{\substack{x \in \mathbb{R}^n \\ \text{s.t.}}} \|x\|_1$$

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$$\begin{array}{ll} \min_{x \in \mathbb{R}^n} & \|x\|_1 \\ \text{s.t.} & Ax = b \end{array}$$

When $t \ge \Omega(\frac{n^3}{\epsilon^2})$, we have (i) $\|\boldsymbol{b} - A\boldsymbol{x}(t)\|_2 \le \epsilon \cdot \|\boldsymbol{b}\|_2$ and (ii) $\|\boldsymbol{x}(t)\|_1 - \|\boldsymbol{x}^*\|_1 \le \epsilon \cdot \|\boldsymbol{x}^*\|_1$.

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$$\begin{split} \min_{\substack{x \in \mathbb{R}^n \\ \text{s.t.}}} & \|x\|_1 \\ \text{s.t.} & Ax = b \end{split} \\ \end{aligned}$$

$$\begin{aligned} \text{When } t \geq \Omega(\frac{n^3}{\epsilon^2}) \text{, we have (i) } \|b - Ax(t)\|_2 \leq \epsilon \cdot \|b\|_2 \text{ and} \\ \text{(ii) } \|x(t)\|_1 - \|x^*\|_1 \leq \epsilon \cdot \|x^*\|_1. \end{aligned}$$

	Primal SNN	Dual SNN
Dynamics	$\boldsymbol{u}(t+1) = \boldsymbol{u}(t) - \begin{pmatrix} A^{T}A & -A^{T}A \\ -A^{T}A & A^{T}A \end{pmatrix} \boldsymbol{s}(t) + \begin{pmatrix} A^{T}\boldsymbol{b} \\ -A^{T}\boldsymbol{b} \end{pmatrix}$	
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Optimization problem	$ \min_{\boldsymbol{x} \in \mathbb{R}^n} \ \boldsymbol{x}\ _1 $ (ℓ_1 minimization) s.t. $A\boldsymbol{x} = \boldsymbol{b}$	

	Primal SNN	Dual SNN
Dynamics	$\boldsymbol{u}(t+1) = \boldsymbol{u}(t) - \begin{pmatrix} A^{T}A & -A^{T}A \\ -A^{T}A & A^{T}A \end{pmatrix} \boldsymbol{s}(t) + \begin{pmatrix} A^{T}\boldsymbol{b} \\ -A^{T}\boldsymbol{b} \end{pmatrix}$	$\boldsymbol{v}(t+1) = \boldsymbol{v}(t) - (A - A)\boldsymbol{s}(t) + \boldsymbol{b}$
Optimization problem	$ \min_{\boldsymbol{x} \in \mathbb{R}^n} \ \boldsymbol{x}\ _1 $ s.t. $A\boldsymbol{x} = \boldsymbol{b}$ (ℓ_1 minimization)	

	Primal SNN	Dual SNN	
Dynamics	$\boldsymbol{u}(t+1) = \boldsymbol{u}(t) - \begin{pmatrix} A^{T}A & -A^{T}A \\ -A^{T}A & A^{T}A \end{pmatrix} \boldsymbol{s}(t) + \begin{pmatrix} A^{T}\boldsymbol{b} \\ -A^{T}\boldsymbol{b} \end{pmatrix}$	$\boldsymbol{v}(t+1) = \boldsymbol{v}(t) - (A - A)\boldsymbol{s}(t) + \boldsymbol{b}$	
Optimization problem	$ \min_{\boldsymbol{x} \in \mathbb{R}^n} \ \boldsymbol{x}\ _1 $ s.t. $A\boldsymbol{x} = \boldsymbol{b}$ (ℓ_1 minimization)	$\begin{array}{ll} \max_{\boldsymbol{v} \in \mathbb{R}^m} \boldsymbol{b}^{T} \boldsymbol{v} & \text{(The dual of} \\ \text{s.t. } \ \boldsymbol{A}^{T} \boldsymbol{v}\ _{\infty} \leq 1 \ell_1 \text{ minimization)} \end{array}$	

	Primal SNN	Dual SNN	
Dynamics	$\boldsymbol{u}(t+1) = \boldsymbol{u}(t) - \begin{pmatrix} A^{T}A & -A^{T}A \\ -A^{T}A & A^{T}A \end{pmatrix} \boldsymbol{s}(t) + \begin{pmatrix} A^{T}\boldsymbol{b} \\ -A^{T}\boldsymbol{b} \end{pmatrix}$	$\boldsymbol{v}(t+1) = \boldsymbol{v}(t) - (A - A)\boldsymbol{s}(t) + \boldsymbol{b}$	
Optimization problem	$ \min_{\boldsymbol{x} \in \mathbb{R}^n} \ \boldsymbol{x}\ _1 $ s.t. $A\boldsymbol{x} = \boldsymbol{b} $ (ℓ_1 minimization)	$\begin{array}{ll} \max_{\boldsymbol{v} \in \mathbb{R}^m} \boldsymbol{b}^{T} \boldsymbol{v} & \text{(The dual of} \\ \text{s.t. } \ A^{T} \boldsymbol{v}\ _{\infty} \leq 1 \ell_1 \text{ minimization)} \end{array}$	

v(t) is a projected gradient descent algorithm for dual program with non-standard projection.

Key Technique – A Dual View of SNN			External ch ≈ Gradie	arging nt	
	Primal SNN		Dual S	NN	
Dynamics	$\boldsymbol{u}(t+1) = \boldsymbol{u}(t) - \begin{pmatrix} A^{T}A & -A^{T}A \\ -A^{T}A & A^{T}A \end{pmatrix} \boldsymbol{s}(t) + \begin{pmatrix} A^{T}\boldsymbol{b} \\ -A^{T}\boldsymbol{b} \end{pmatrix}$	v(t +	$1) = \boldsymbol{v}(t) - (A$	$-A)\mathbf{s}(t)$	+ <i>b</i>
Optimization problem	$ \min_{\boldsymbol{x} \in \mathbb{R}^n} \ \boldsymbol{x}\ _1 $ s.t. $A\boldsymbol{x} = \boldsymbol{b} $ (ℓ_1 minimization)	$\max_{\boldsymbol{v}\in\mathbb{R}^m} \boldsymbol{b}$ s.t. A	$\ \mathbf{v} \ _{\infty} \leq 1$	(The ℓ_1 mini	dual of imization)
		v(t) is a	a projected g	radient	descent

non-standard projection.

Key Teo	chnique – A Dual View of S	Spiking effect ≈ Projection
	Primal SNN	Dual SNN
Dynamics	$\boldsymbol{u}(t+1) = \boldsymbol{u}(t) - \begin{pmatrix} A^{T}A & -A^{T}A \\ -A^{T}A & A^{T}A \end{pmatrix} \boldsymbol{s}(t) + \begin{pmatrix} A^{T}\boldsymbol{b} \\ -A^{T}\boldsymbol{b} \end{pmatrix}$	$\boldsymbol{v}(t+1) = \boldsymbol{v}(t) - (A - A)\boldsymbol{s}(t) + \boldsymbol{b}$
Optimization problem	$ \min_{\boldsymbol{x} \in \mathbb{R}^n} \ \boldsymbol{x}\ _1 $ s.t. $A\boldsymbol{x} = \boldsymbol{b} $ (ℓ_1 minimization)	$\max_{\boldsymbol{v} \in \mathbb{R}^m} \boldsymbol{b}^{T} \boldsymbol{v} \qquad \text{(The dual of s.t. } \ A^{T} \boldsymbol{v}\ _{\infty} \leq 1 \ell_1 \text{ minimization)}$
		 v(t) is a projected gradient descent algorithm for dual program with non-standard projection.

	Primal SNN		Primal SNN Dual SNN		NN
Dynamics	$\boldsymbol{u}(t+1) = \boldsymbol{u}(t) - \begin{pmatrix} A^{T}A \\ -A^{T}A \end{pmatrix}$	$ \frac{-A^{T}A}{A^{T}A} \mathbf{s}(t) + \begin{pmatrix} A^{T}\mathbf{b} \\ -A^{T}\mathbf{b} \end{pmatrix} $	$\boldsymbol{v}(t+1) = \boldsymbol{v}(t) - (A$	$-A)\mathbf{s}(t) + \mathbf{b}$	
Optimization problem	$\min_{\boldsymbol{x} \in \mathbb{R}^n} \ \boldsymbol{x}\ _1$ s.t. $A\boldsymbol{x} = \boldsymbol{b}$	ℓ_1 minimization)	$\max_{\boldsymbol{v} \in \mathbb{R}^m} \boldsymbol{b}^{T} \boldsymbol{v}$ s.t. $\ A^{T} \boldsymbol{v}\ _{\infty} \leq 1$	(The dual of ℓ ₁ minimization)	
The firing solves the	rate in primal SNN e primal program.	KKT conditions	<pre>v(t) is a projected g algorithm for dual non-standard</pre>	gradient descent program with projection.	
Key Technique – A Dual View of SN		SNN Spikes are non-monotone and difficult to analyze!			
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	Primal SNN	Dual SNN			
Dynamics	$\boldsymbol{u}(t+1) = \boldsymbol{u}(t) - \begin{pmatrix} A^{T}A & -A^{T}A \\ -A^{T}A & A^{T}A \end{pmatrix} \boldsymbol{s}(t) + \begin{pmatrix} A^{T}\boldsymbol{b} \\ -A^{T}\boldsymbol{b} \end{pmatrix}$	$\boldsymbol{v}(t+1) = \boldsymbol{v}(t) - (A - A)\boldsymbol{s}(t) + \boldsymbol{b}$			
Optimization problem	$ \min_{\boldsymbol{x} \in \mathbb{R}^n} \ \boldsymbol{x}\ _1 $ s.t. $A\boldsymbol{x} = \boldsymbol{b}$ (ℓ_1 minimization)	$ \max_{\boldsymbol{v} \in \mathbb{R}^m} \boldsymbol{b}^{T} \boldsymbol{v} $ (The dual of s.t. $\ A^{T} \boldsymbol{v}\ _{\infty} \leq 1$ ℓ_1 minimization)			
The firing i solves the	rate in primal SNN e primal program. KKT conditions Perturbation theory	 v(t) is a projected gradient descent algorithm for dual program with non-standard projection. 			

Perspectives – Natural Algorithms

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Through the lens of natural algorithms, can we understand SNNs more via its algorithmic power and even discover new algorithmic ideas?

In this work, we show that integrate-and-fire SNN uses its firing rate to efficiently solve some optimization problems in a primal-dual way!

• In this work, we give the first proof for the firing rate of integrate-and-fire SNNs efficiently solving non-negative least squares problem and ℓ_1 minimization problem.

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- Related works.
 - Universality and computational complexity.
 - SNN is able to simulate Turing machines, random access machines (RAM), and threshold circuits etc. [Maa96, Maa97b, Maa99, MB01].
 - Using SNNs to solve computational/optimization problems.
 - Sparse coding [ZMD11, Tan16, TLD17], dictionary learning [LT18], pattern recognition [DC15, KGM16, BMF+17], and non-negative least squares[BDM13].
 - Implementing MCMC to solve traveling salesman problem (TSP) and constraint satisfaction problem (CSP) [BBNM11, JHM14, Maa15, JHM16].
 - Assemblies of neurons and random projection [ADMPSV18, LPVM18, PV19].
 - The efficiency of SNNs in solving computational problems.
 - Solving Winner-Take-All (WTA) problem, similarity testing, and neural coding [LMP17a, LMP17b, LMP17c, LM18].

Very few works provide provable analysis on the efficiency of SNN algorithms!

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