(Almost) Practical Tree Codes

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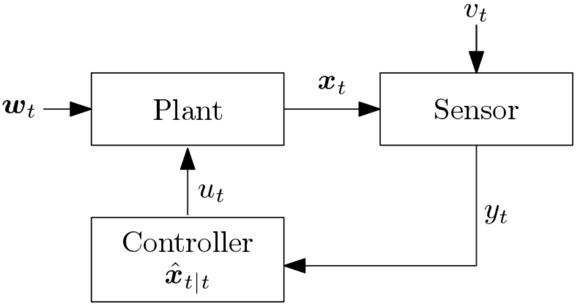
Networked Control vs. Traditional Control

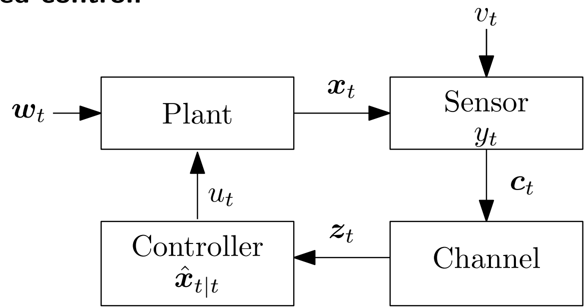
Traditional control:



- Observer and controller are co-located.
- Classical systems are hardwired and well crafted

Networked Control vs. Traditional Control

Networked control:

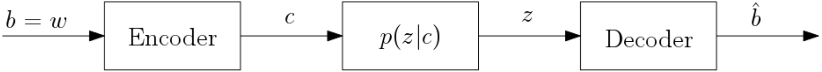


- Observer and controller are not co-located: connected through noisy link
- Suitable for new remote applications (e.g., remote surgery, self-driving cars)

Motivating Example: Tracking a Random Walk [Sahai PhD'01]

$$x_{t+1} = \alpha x_t + w_t$$

- $\alpha > 1 \implies$ not stable!
- $w_t \in \{\pm 1\}$
- We wish to track x_t with bounded expected distortion
- If tracking is possible, stability usually follows
- Allows to distill the coding problem (no quantization)



Distortion requirement

$$\mathbb{E}\left[(x_t - \hat{x}_t)^2\right] < \infty, \qquad \forall t$$

Motivating Example: Tracking a Random Walk [Sahai PhD'01]

- $\hat{b}_{t-d|t}$ – Estimate of b_{t-d} at time t
- Probability of first error event at time $t-d$:
  $P_e(t,d) \triangleq \Pr\left(b_{t-d} \neq \hat{b}_{t-d|t}, \forall \delta > d, b_{t-\delta} = \hat{b}_{t-\delta|t}\right)$

$$\mathbb{E}\left[\left(x_t - \hat{x}_{t|t}\right)^2\right] \propto \sum_{d=1}^{t} P_e(t,d)\alpha^{2d} = \sum_{d=1}^{t} P_e(t,d) 2^{2\log\alpha\cdot d} < \infty$$

Error probability profile: Anytime-reliable code

$$P_e(t,d) < 2^{-(2\log\alpha+\epsilon)d}, \qquad \forall t, d_0 < d < t$$

Larger moments

Higher exponent $\Longrightarrow$ Cannot stabilize all moments!

Anytime-Reliable Codes: Basics

Error probability profile

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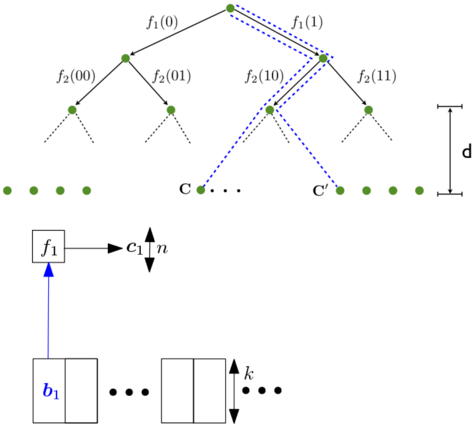
How to generate such a code?

$$\begin{aligned} \boldsymbol{c}_1 &= f_1(\boldsymbol{b}_1) \\ \boldsymbol{c}_2 &= f_2(\boldsymbol{b}_1, \boldsymbol{b}_2) \\ &\vdots \\ \boldsymbol{c}_t &= f_t(\boldsymbol{b}_1, \boldsymbol{b}_2, \ldots, \boldsymbol{b}_t) \\ &\vdots \end{aligned}$$



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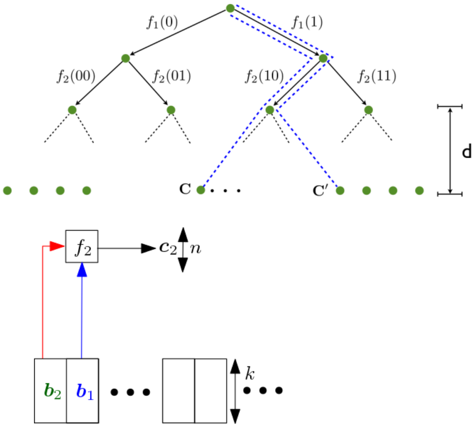

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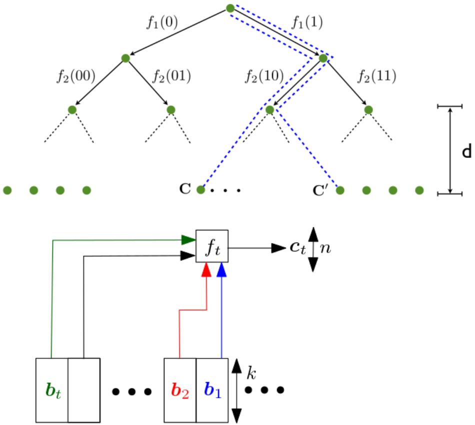


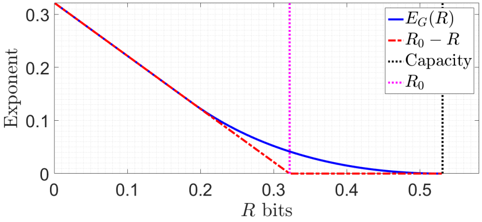
Anytime-Reliable Codes as Convolutional Codes

Random time-varying convolutional-code ensemble [Viterbi, Yudkin, Zigangirov, Shulman–Feder, ...]

- Most results assume infinite stream ($\gg$ delay-line length)
- We wish to recover a bit using subsequent *nd* output symbols
- The random time-varying CC ensemble achieves:

$$\mathbb{E}[P_e(t,d)] \leq 2^{-E_G(R)nd}$$

- $E_G(R) > 0$ for $R < C$ – Gallager's error exponent



Anytime-Reliable Codes as Convolutional Codes

Good ensemble performance $\Rightarrow$ Good specific code performance?

- Block codes: Yes, with high probability!
- Anytime reliable-code?
- Such a code exists [Schulman IT'96], but **not w.h.p.** ☹
  (Proof requires min-distance $\propto$ delay)
- **How to construct a good anytime-reliable code?**

Ensemble Performance ⇒ Specific Code Performance?

Ensemble performance

$$\mathbb{E}[P_e(t,d)] \le 2^{-E_G(R)nd}$$

Specific d and t

Using Markov's inequality:

$$\Pr\left(P_e(t,d) \ge 2^{-[E_G(R)-\epsilon]nd}\right) \le \frac{\mathbb{E}[P_e(t,d)]}{2^{-[E_G(R)-\epsilon]nd}} = 2^{-\epsilon nd}$$

Ensemble Performance $\Rightarrow$ Specific Code Performance?

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Linear Time-Invariant Codes [Sukhavasi–Hassibi ISIT'11]

Linear time-variant code

$$\mathbf{G} = \begin{bmatrix} \mathbf{G}_{1,1} & \mathbf{0} & \cdots & \cdots & \cdots \\ \mathbf{G}_{2,1} & \mathbf{G}_{2,2} & \mathbf{0} & \cdots & \cdots \\ \vdots & \vdots & \ddots & \ddots & \cdots \\ \mathbf{G}_{t,1} & \mathbf{G}_{t,2} & \cdots & \mathbf{G}_{t,t} & \mathbf{0} \\ \vdots & \vdots & \vdots & \vdots & \ddots \end{bmatrix}$$

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All t and $d_0 < d \leq t$

Using the union bound:

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$$= \frac{2^{-\epsilon n d_0}}{1 - 2^{-\epsilon n}}$$

Linear Time-Invariant Codes

- Random LTI convolutional codes are anytime-reliable w.h.p. ✓
- But the exponent result was valid for time-variant codes
- Valid also for LTI codes [S~~c~~hulman–Feder IT'00] ✓
  - (Proved independently in [Sukhavasi–Hassibi ISIT'11])
- **No gain** for general codes over LTI codes in this regime!
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What about decoding?

Decoding of Linear Time-Invariant Codes

- All results assumed maximum-likelihood (ML) decoding
- ML complexity rises exponentially with t

Binary Erasure Channel (BEC)

- For LTI codes: ML $=$ Solving linear equations

- What about other channels?

Sequential Decoding

- Before Viterbi algo.: Sequential decoding *de facto* standard
- Sequential decoding = class of algorithms
- Introduced originally in [Wozencraft '57] for **tree codes**
- Common to all: Explore only subset of (likely) codewords
- Most prominent variants: Stack and Fano's algorithms

Sequential Decoding

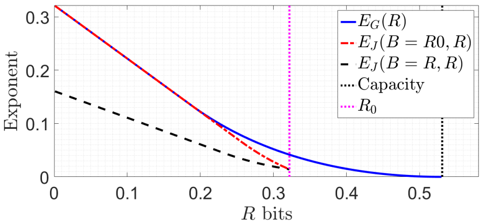
- Fano's metric: $M(\boldsymbol{c}_1, \cdots, \boldsymbol{c}_t) = \sum_{i=1}^{nt} \left[\log \frac{p(z_t|c_t)}{p(z_t)} - \overbrace{B}^{\text{bias}} \right]$
- For ML decoding: $\arg\max_{\{\boldsymbol{c}_i\}} p(z_t|c_t) = \arg\max_{\{\boldsymbol{c}_i\}} \left[\log \frac{p(z_t|c_t)}{p(z_t)} - B \right]$
- For partial tree exploration: Fano's metric penalizes longer incorrect paths via bias B

Sequential Decoding: Error Probability

Error probability of **general** conv. ensemble [Jelinek's Book '68]

$$\mathbb{E}[P_e(t,d)] \le A\,2^{-E_J(B,R)nd}$$

- A is finite for $B < R_0$
- $E_J(B,R)$ properties:
  - $\frac{1}{2}E_G(R) \le E_J(B,R) < E_G(R)$
  - $E_J(B,R) \xrightarrow{B \to R_0} E_G(R)$, for $R < R_{\text{crit}}$
- Does not guarantee a good **specific code** w.h.p.



Sequential Decoding: Error Probability

Proof for general codes requires:

- **Pairwise independence:** Every two paths are independent (from divergence point)
- **Individual codeword distribution:** Entries within each codeword are i.i.d.

Sequential Decoding: Error Probability

Use the following affine time-invariant ensemble:

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- Entries of $\{\mathbf{G}_t\}$, $\{\boldsymbol{b}_t\}$ and $\{\boldsymbol{v}_t\}$ are i.i.d. uniform
- $\{\boldsymbol{v}_t\}$ random translation vectors

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Sequential Decoding: Complexity

- W_t – Number of branch computations of note t
- W_t is a random variable

Cutoff rate [Arıkan IT'88]

For any "good" code (general or LTI), $\mathbb{E}[W_t]$ is unbounded for $R > R_0$.

Pareto distribution of W_t [Gallager, Zigangirov, Viterbi–Omura, ...]

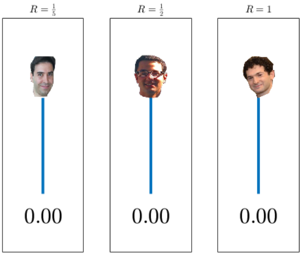
$$\Pr\left(W_t \geq m\right) \leq Am^{-\rho}$$

- For $B, R < R_0$ and $R < \frac{B+\mathrm{R}_0}{2\rho}$, $\rho \in (0, 1]$:
  Tight for **general** and **LTI** codes $\Rightarrow \mathbb{E}[W_t] < \infty$ for $R < R_0$
- For $\rho > 1$, $R = E_0(\rho)/\rho$:
  - Tight for **general** codes
  - Widely conjectured to be true for **LTI** codes
- Heavy tailed even if expectation is finite!

Simulation: Cart–Stick over BSC(0.01)

$$n = 20$$

$k =$	4	10	20
$R =$	$\frac{1}{5}$	$\frac{1}{2}$	1
$E =$	0.5382	0.2382	0



- Cart–stick system model [Franklin–Powell–Emami-Naeini Book]
- BSC(0.01)
- For this setting [Sukhavasi–Hassibi ISIT'11]: $k_{\min} = 3$, $E_{\min} = 0.2052$