

## Estimation of nonspecificity in the Dempster-Shafer theory.

Pavla Kunderová

Department of mathematical analysis and numerical mathematics,  
Palacký University Olomouc, Czech Republic

*Nonspecificity is one of the measures of uncertainty in the Dempster-Shafer theory. Point and interval estimations of nonspecificity were suggested in this article.*

*Keywords: Dempster-Shafer theory, uncertainty, nonspecificity.*

### 1. Terminology and notations.

Let  $X$  denote a universal set under consideration assumed here to be finite. Semantically  $X$  represents the set of all possible answers to a question (all possible states of a system, all possible diagnoses). We assume that elements of  $X$  are mutually exclusive answers (states, diagnoses). Let  $\mathcal{P}(X)$  denote the power set of  $X$ . Subsets of  $X$  are identified with propositions ( $A \subseteq X$  is identified with the proposition "the true answer is in  $A$ "). The Dempster-Shafer theory is based upon a function

$$m: \mathcal{P}(X) \longrightarrow \langle 0, 1 \rangle$$

such that

$$m(\emptyset) = 0 \quad \text{and} \quad \sum_{A \subseteq X} m(A) = 1 \quad .$$

This function is called a *basic belief assignment* (or just *basic assignment*). The value  $m(A)$  represents the degree of belief that a specific element of  $X$  belongs to set  $A$ , but not to any particular subset of  $A$ . Every set  $A \in \mathcal{P}(X)$  for which  $m(A) \neq 0$  is called a *focal element*. The pair  $(F, m)$ , where  $F$  denotes the set of all focal elements of  $m$ , is called a *body of evidence*.

Two distinct types of uncertainty are subsumed in the Dempster-Shafer theory. One of them is well characterized by the name *nonspecificity*. This type of uncertainty is properly measured by a function  $N$  defined by the formula

$$N(m) = \sum_{A \in F} m(A) \log_2 |A| ,$$

where  $|A|$  denotes the cardinality of the focal element  $A$ . This function was proven to be unique under appropriate requirements [3].

It measures nonspecificity of a body of evidence in units that are called *bits*.

One bit of uncertainty expresses the total ignorance regarding the truth or falsity of one proposition. It is obvious that the function  $N(m)$  attains its minimum,  $N(m)=0$ , if and only if all focal elements are singletons (  $N(m) = 0$  for all probability measures ). The maximum of  $N(m)$  is attained when  $m(X) = 1$ , then  $N(m) = \log_2 |X|$ . Hence the range of  $N(m)$  is

$$0 \leq N(m) \leq \log_2 |X| .$$

## 2. Estimations of $N(m)$ .

There is a natural question: how to estimate the unknown value of  $N(m)$  in the practice?

Let  $Y = \{A_1, \dots, A_r\}$  be a system of all non-empty subsets of the universal set  $X$ .

Let us repeat  $n$  independent experiments such that the result of each experiment consists in determination of one and only one element of a system  $Y$ .

### Example.

A patient is suffering from a certain disease belonging to a set  $X$ . He will be examined by  $n$  (independent) doctors. Each of them determines one non-empty subset of  $X$  to which, according to him, the disease of the patient belongs.

Let  $\xi_{ji}$  be a random variable defined as follows:

$\xi_{ji} = 1$  in case the subset  $A_j$  is chosen in the  $i$ -th experiment,  
 $\xi_{ji} = 0$  in case the subset  $A_j$  is not chosen in the  $i$ -th experiment.

Let 
$$Z_j = \sum_{i=1}^n \xi_{ji}, \quad j=1, \dots, r,$$

thus the random vector  $(Z_1, \dots, Z_r)$  has the multinomial distribution with parameters  $n, p_1=m(A_1), \dots, p_r=m(A_r)$ .

Theorem 1.

The random variable

$$\hat{m}(A_j) = \frac{Z_j}{n}, \quad j=1, \dots, r,$$

is an unbiased estimation of  $m(A_j)$ ,  $j=1, \dots, r$ ,

and the random variable

$$\hat{N}(m) = \sum_{A \subseteq X, A \neq \emptyset} \hat{m}(A) \log_2 |A|,$$

is an unbiased estimation of a nonspecificity  $N(m)$ .

*Proof.* Obvious by using the definition of  $Z_j$ ,  $j=1, \dots, r$ .

In the following we shall derive a confidence interval of the nonspecificity  $N(m)$ . Let us consider two probability distributions

$$P = \{p_1 = m(A_1), \dots, p_r = m(A_r)\}, \quad \hat{P} = \{\hat{p}_1 = \hat{m}(A_1), \dots, \hat{p}_r = \hat{m}(A_r)\},$$

on the space

$$Y = (A_1, \dots, A_r) = (y_1, \dots, y_r).$$

Let us consider a random variable  $\xi$  defined on the probability space  $(Y, P)$  and its mathematical expectations under  $\hat{P}$  and  $P$

$$E_{\hat{P}}(\xi) = \sum_{i=1}^r \xi(y_i) \hat{p}_i, \quad E_P(\xi) = \sum_{i=1}^r \xi(y_i) p_i.$$

and the variance under  $P$

$$\sigma_P^2(\xi) = \sum_{i=1}^r [\xi(y_i)]^2 p_i - [E_P(\xi)]^2.$$

Lemma.

If  $\sigma_P^2(\xi) > 0$  then  $\sqrt{n} [E_{\hat{P}}(\xi) - E_P(\xi)]$  tends in law to  $N(0, \sigma_P^2(\xi))$ .

*Proof.* In [1], pg. 13.

Let us define on  $(Y, P)$  a random variable  $\xi$  by

$$\xi(y_i) = \log_2 |A_i|, \quad i = 1, \dots, r,$$

then

$$E_{\hat{P}}(\xi) = \hat{N}(m), \quad E_P(\xi) = N(m),$$

and

$$\sigma_P^2(\xi) = \sum_{i=1}^r [\log_2 |A_i|]^2 m(A_i) - [N(m)]^2.$$

For the sake of simplicity we denote the variance  $\sigma_P^2(\xi)$  by the symbol  $\sigma_m^2$  in what follows.

Theorem 2.

If  $\sigma_m^2 > 0$  then the random variable

$$\sqrt{n} [ \hat{N}(m) - N(m) ]$$

tends in law to the normal distribution  $N(0, \sigma_m^2)$ .

*Proof.* The statement follows by applying the lemma and the definition of the random variable  $\xi$ .

Corollary.

For sufficiently large number  $n$  and for  $\sigma_m^2 > 0$  holds

$$P\left[ \hat{N}(m) - u_{1-\alpha/2} \sigma_m [n]^{-\frac{1}{2}} \leq N(m) \leq \hat{N}(m) + u_{1-\alpha/2} \sigma_m [n]^{-\frac{1}{2}} \right] = 1-\alpha,$$

where  $u_\alpha$  denotes the  $\alpha$ -quantile of the normal distribution  $N(0,1)$ .

Remark.

The unknown value of  $\sigma_m^2$  could be replaced by its estimation

$$\hat{\sigma}_m^2 = \sum_{i=1}^r \hat{m}(A_i) [\log_2 |A_i|]^2 - [\hat{N}(m)]^2.$$

**References.**

- [1] J. Feistauerová, I. Vajda : Testing System Entropy and Prediction Error Probability. In: IEEE Trans. Syst. Man, Cybern. , 1992.
- [2] P. Hájek, D. Harmanec: On belief functions. In: Advances in AI, Lecture notes in AI, Vol 613, 1992, pp. 286 - 307.
- [3] G. J. Klir, T. A. Folger: Fuzzy sets, uncertainty and information, Prentice Hall, Englewood Cliffs (N. J. ), 1988.
- [4] G. J. Klir, A. Remer: Uncertainty in the Dempster-Shafer theory; a critical re-examination. Int. J. General Systems, Vol. 18, pp. 155-166.