

# How we ought to describe computation in the brain

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## 1 Introduction

This essay is structured such that each heading is a specific claim related to quantitative descriptions of brain function. Any subheadings under a given heading are intended to provide additional considerations or details in support of the heading. While this does not provide for typical, smooth, reading of the paper, it serves to make the argument clearer and can shorten reading time, as the content of any “obviously true” heading can be skipped.

The word ‘computation’ is used in a liberal and definitional sense. I am using the liberal sense in the title (the sense typical of cognitive science usage which has no definition and means something like a ‘transformation of representations’). However, I am using the definitional sense (from computational theory) in the remainder of the essay. I will generally replace ‘computation in the brain’ in the first sense with ‘a quantitative description of brain function’ for clarity.

In brief, the argument I present here is:

1. There are four relevant kinds of quantitative description of brain function
2. We ought to provide the best quantitative description of brain function
3. A good description of brain function provides for simple state mappings, and useful decompositions that account for variability
4. A good description in the brain sciences explains by positing mechanisms that support interventions
5. Computation theoretic descriptions do not meet these criteria well, and hence are not good descriptions (from 3, 4)
6. Control theoretic descriptions meet these criteria better than any of the other alternatives (from 3-5).
7. Therefore, control theoretic descriptions are the best descriptions (from 1, 6)
8. Therefore, control theoretic descriptions are the kind of quantitative description we ought to provide (from 2, 7)

One clarification is important: this conclusion does not rule out the other descriptions as useful. Rather, it suggests that other descriptions are essentially heuristics for temporarily stating the description. That is, ultimately, other descriptions should be translated into a unifying description of brain function stated with control theoretic constructs.

## **2 There are four kinds of quantitative description of brain function**

I begin with some considerations regarding how quantitative descriptions relate to physical systems in general, and then turn to which quantitative descriptions are relevant for understanding brain function.

### **2.1 *Different quantitative descriptions are better for different classes of phenomena***

I do not worry about how quantitative descriptions are individuated (i.e., why statistical descriptions are different from dynamical descriptions).

#### **2.1.1 Physical systems can have multiple quantitative descriptions**

In most cases, what we identify as a physical system (e.g. a gas; a computer chip) can be described using different quantitative descriptions (e.g. statistical or Newtonian mechanics; computational theory or circuit theory). If we are trying to argue for *the best* description of some physical system, we must have a means of picking between these possible descriptions.

#### **2.1.2 Quantitative descriptions have a natural class of physical phenomena that they describe**

Notably, many descriptions are of the same mathematical class (e.g. both computational and circuit descriptions are algebraic), so it is not their mathematical properties that distinguish them.

Instead, it is the agreed upon mapping between the mathematics and the physical world which aligns with the different kinds of quantitative descriptions available. So, in circuit theory, variables are measurable properties like resistance, current, and voltage, whereas in computational theory variables are easily distinguished system states, like low/high voltage, or open/closed (mechanical) gates.

In essence, this is why they are a quantitative descriptions *of* something: there is a defined mapping from the description to physical states. Such mappings are natural (i.e. simple, straightforward, easy for us to understand) for the class of phenomena that they are explicitly defined over (and to the extent those definitions are specific). For instance, circuit descriptions are natural over the class of voltages, currents, etc. They are no more specific (i.e. picking out material properties) or less specific (i.e. picking out non-electrical properties like fluid flow).

These considerations result in the unsurprising conclusion that quantitative descriptions are natural for the class of physical systems they are explicitly defined to be descriptions of.

#### **2.1.3 Quantitative descriptions are implementation independent, but to differing degrees**

As is again evident from the computation versus circuit descriptions, some quantitative descriptions (e.g. circuit theory) apply only to a subclass of others (e.g. computational

theory). As a result, computational theory is more implementation independent than circuit theory. Notice also that circuit theory is independent of many specific material properties of potential circuit elements, for which chemical descriptions may be most natural.

#### **2.1.4 The goodness of a description varies depending on the phenomena of interest**

I have more to say on what constitutes a good description in section 3. These considerations can be preliminary given an agreed upon characterization of goodness.

If the agreed upon notion of goodness is partly psychological (e.g. relies on simplicity), and the natural class for a description is as well (e.g. also relying on simplicity), then the goodness of a description will vary depending on the natural class of phenomena in question. A description will be best for the phenomena which fall most directly in its natural class.

Just to be clear, this principle does not result in unbridled relativism: so long as we have a consistent measure of goodness across all phenomena, there will be one description which is best for a given class.

## ***2.2 There are four kinds of quantitative description relevant to brain function***

Here, I briefly describe each approach, indicate the class of systems it is most natural for, and describe its type of implementation independence.

### **2.2.1 Computational**

Computational descriptions adopt computational theory which characterizes systems using Turing languages. Such languages are able to describe any Turing Machine computable function. I take this to have historically been the dominant approach in cognitive science.

#### *2.2.1.1 The natural physical phenomena for computational descriptions are those that are easily discretizable*

What I have called Turing languages assume a mapping between the description in the language and distinct physical states. The paradigm case of this is the high/low voltages of silicon transistors mapped to 1s and 0s in the description. In general, any physical system which has easily distinguished (i.e., discrete in both space and time) states can be well-described by such languages. Often such systems are engineered.

#### *2.2.1.2 Computational descriptions are highly implementation independent*

Turing Machines are a powerful computational description precisely because they are completely implementation independent. Much has been made of this by functionalists in cognitive science. Notably, this independence means that certainty of the state value is generally assumed (i.e. that it is either 1 or 0). In short, randomness, or noise is typically ignored.

## 2.2.2 Dynamical

Dynamical systems theory, as a mathematical theory is extremely general (and arguably equivalent to control theory). However, in the context of cognitive systems, a number of researchers have championed the ‘dynamical systems theory of mind,’ which I refer to as DST. DST uses the mathematical theory, but adds additional assumptions when applying it to cognitive systems. Given the equivalence between the mathematical theory and control descriptions, I will discuss DST unless otherwise noted.

### *2.2.2.1 The natural physical phenomena for DST dynamical descriptions is simple phenomena governed by physical laws*

Simplicity is a stated assumption of DST theorists in cognitive science: van Gelder and Port (1995) argue that DST theorists must “provide a *low-dimensional* model that provides a scientifically tractable description of the same qualitative dynamics as is exhibited by the high-dimensional system (the brain).” This constraint of low-dimensionality is severe, and limits the complexity of such descriptions to simple systems. However, such systems, being continuous, are strictly more computationally powerful than TMs.

### *2.2.2.2 DST dynamical descriptions are implementation independent*

In DST, the low-dimensional descriptions are implementation independent, because they rely on ‘lumped parameters.’ Such parameters are high-level, non-physical parameters necessary to match dynamics, generally uninformed by implementational constraints.

## 2.2.3 Statistical

Statistical descriptions describe the probability of various measurable states of the system given other known states of the system. Such models usually have as their central goal the prediction of data.

### *2.2.3.1 The natural physical phenomena for statistical descriptions is complex phenomena with unknown mechanisms*

Complex systems, in virtue of their complexity, often have many unknown or undescribed interactions between system components. As a result, starting from given initial conditions often maps to a wide possibility of subsequent states. Statistical models are ideal for describing systems of this kind when prediction is of the utmost importance (e.g. in data analysis). Notably, not describing mechanisms explicitly generally has the cost of making novel interventions difficult to predict.

### *2.2.3.2 Statistical descriptions are highly implementation independent*

Statistical models focus on describing the regularities in the data, and hence are silent with respect to the particular physical implementation. In essence, these descriptions will not change if only implementation changes (and statistical properties do not). Another way of describing this tendency is by noting that the model is often highly specific to a given data set. This is consistent with implementation independence because implementation and the values of measured system states (data) are usually tightly coupled, though they do not *have* to be.

## 2.2.4 Control theoretic

Control theoretic descriptions describe the dynamics of a system through its state space. Usually, the notions of ‘controller’ and ‘plant’ are used to describe the system.

*2.2.4.1 The natural physical phenomena for control theoretic descriptions are those with directed dynamics*

Because of the usual distinction between plants and controllers, control theoretic descriptions typically apply to systems in which one part of the system directs the dynamics of another part of the system. Control theory uses the general tools of mathematical dynamical systems theory.

*2.2.4.2 Control theoretic descriptions vary between implementation independent and implementation specific*

Standard (i.e. general mathematical) dynamical analyses are performed in a manner which precisely removes the physical uniqueness of the problem (e.g. through non-dimensionalization, and using normal form analysis). In this sense, many such descriptions are intentionally implementation independent. However, they are so explicitly by design, not by the nature of the description. As a result, the original equations that are often parametrically tied to specific physical instantiations (e.g. a circuit, or a circuit in silicon, etc.) can also be used as a system description. In such a case, the description is highly implementation specific.

Thus control theory can describe implementation independent controllers, while also being crucial for describing particular implementations of those controllers in a given medium.

## 2.3 *Some of these quantitative descriptions are strictly equivalent*

### 2.3.1 **Control theoretic descriptions are equivalent to dynamical and statistical descriptions**

This is merely the mathematical observation that all of these approaches employ methods defined over the reals, and have no evident restrictions on the functions that they can compute in that domain (the restriction of unity integrals on statistical descriptions, is not significant as it is still uncountable). This makes all of these descriptions strictly more powerful than TMs.

### 2.3.2 **Computational descriptions are strictly weaker than the other options**

TM languages are strictly weaker than those defined over the continuum (Siegelmann, 1995). Finite state automata (FSAs) are weaker still.

### 2.3.3 **Brain function *can* be described by any of these candidates**

As I have argued in detail elsewhere (Eliasmith, 2000), given the ubiquitous presence of noise in the brain, only a finite amount of information can be passed between the outside world and brain states, or between brain states. As a result, TMs are sufficient for describing the information processing properties of the brain. In fact, FSAs are also sufficient, as the difference between them and TMs is that TMs have infinite resources

(tape and time). Brains clearly do not share that luxury. So, FSAs can describe all brain-computable functions.

Since FSAs can describe all brain-computable functions, and since all of the considered descriptions are strictly more powerful than FSAs, all of the considered descriptions can describe brain function. Hence, brain function is the kind of phenomena that has multiple descriptions (see section 2.1.1), so *we must turn to other criteria to determine which is the best.*

## **2.4 *There are no other relevant candidates***

There are no other candidates for two reasons: 1) possible candidates are equivalent to what has been discussed; or 2) possible candidates have not been shown to be generally useful to the description of cognitive systems. Examples of the first type are most logics (equivalent to computational descriptions) and quantum theory (equivalent to continuous descriptions). Examples of the second type include quantum theory (despite the supposed theories of consciousness, no quantum explanations of cognitive system function for even simple tasks have been offered) and hybrid descriptions. I am not aware of serious, non-interim hybrid descriptions of cognitive systems. In general, hybrid descriptions are temporary because they violate the general assumption that a general description should be unified. If this is not assumed a set of non-arbitrary rules for determining when to use which (sub)description must also be offered. I will assume throughout that descriptive unification is a defining feature of a good description.

## **3 A good description of brain function provides for simple state mappings and decompositions, which account for variability**

Because each of the considered quantitative descriptions is both general and theoretically powerful enough to describe brain function, we must adjudicate their applicability via other criteria. Here I argue for several criteria that constitute a good description of brain function. This is not intended to be ‘good in all possible senses’ (see section 4.3), but rather ‘good for successful cognitive scientific theories’.

### **3.1 *A good description provides a simple mapping from data to description states***

In order for a description to be useful, it must be practical to map between the states identified by the description, and the means of identifying such states within the relevant sciences. The simpler such a mapping is, the better (because more practical) the description becomes. The mapping is more practical because it is evident how new information can be integrated with, or challenges, the currently accepted description.

If it is difficult, or impossible, to determine how new evidence informs the theory we have described quantitatively, then the theory itself is lacking. This, of course, is to be evaluated relative to other offered quantitative theories.

### ***3.2 A good description provides a clear decomposition of the system***

Ideally, a quantitative description can act as a guide to a useful means of decomposing the system. Because of the complexity of neural systems, decomposition is an essential explanatory strategy (Bechtel and Richardson, 1993). The more specific and effective the decomposition for explanatory progress, the better the description.

### ***3.3 A good description accounts for variability***

If the type of system to which the description applies is a broad, variable class (as in the case of neural systems), then descriptions able to explicitly incorporate this variability will be better than those that do not. Characterizing the precise form and effect of the variability is crucial in the case of complex systems, which generally have significant amounts of unexplained (sometimes unexplainable) behaviour. In addition, the precise nature of the variability can be highly sensitive to implementational constraints. Thus descriptions sensitive to implementation are often more able to explain the relevant variability than those that are not.

## **4 A good description explains by positing mechanisms that support interventions**

A good description is one which satisfies scientific goals. In cognitive and brain science, I take those goals to include explanation, prediction, and identification of mechanisms in order to reproduce and intervene in the complex behaviours of neurobiological systems. A good descriptive strategy will be applicable at many levels of fine-grainedness and be able to relate (i.e. unify) the relevant levels.

### ***4.1 Cognitive science aims at explaining and predicting behaviour***

Cognitive science has a focus on explaining the underpinnings of behaviour. While the appropriate level at which such a description needs to be given has been a matter of much debate, the aim itself has not been. As a result, any good description must be both explanatory and predictive of behaviour.

### ***4.2 Explanatory means mechanistic***

In the case of cognitive and brain sciences, useful explanations are those that appeal to subpersonal mechanisms. This is because it is precisely such explanations which provide a basis for both intervention in behaviour and the artificial reproduction of those behaviours. These mechanisms must be specific enough to allow for intervention. That is, the mechanisms must be specified in a way that relates to the measurable and manipulable properties of the system.

### ***4.3 There are other definitions of 'good'***

Sections 3 and 4 are the antecedent of a conditional. That is, if we take good descriptions to be of this nature, then we ought to employ control theoretical descriptions of brain function. As such, there is no need to defend this as the best or only definition of 'good'; and I intend not to. Like any argument, the conclusion follows in so far as the antecedent

is taken to be true. Hopefully, this definition of ‘good’ is plain enough to be generally acceptable.

## **5 Computational descriptions do not satisfy these criteria well**

Here I evaluate computational descriptions with respect to the previous criteria for determining what is a good quantitative description of brain function. I suggest that computational descriptions are not especially good. This is only relevant if there is a better description. In section 6, I argue that control theoretic descriptions are better.

### ***5.1 Mappings from data to computational states is complex***

#### **5.1.1 Single cell models are more simply described as dynamical systems**

In short, this is because the brain does not functionally discretize well. The earliest attempts to suggest possible discretizations include the McCulloch and Pitts (1943) model of the single cell. Their mapping between logic gates and neurons was not intended to be physiologically plausible, and it clearly is not. There have not been other serious attempts to do so.

Perhaps the reason is that even if a state table were available for such a neuron, it is not informative as to the biological mechanisms that are described by that table. While the information transfer characteristics of neurons suggests that about 1-3 bits of information is transferred per action potential (Reike et al., 1997), the relationship between input and output bits is not naturally described by a neuron model with discrete states and logic-like transitions. Instead, the simplest neuron models take the form of dynamical descriptions (which can be ‘translated’ into computational ones, but become much more complex in so doing). These descriptions have variables and parameters directly mapped to the physical properties of single cells, such as cell membrane capacitance, membrane resistance, and ion flux.

#### **5.1.2 Neural methods do not provide easily discretized data sets**

When we turn to other kinds of available data (than single cell spike trains), be it measured electrical properties of individual cells, or of large portions of cortex (EEG, fMRI, MEG), or of observable motor behaviour, the problem seems worse. All of these kinds of data are generally analyzed as continuous signals, because discretizations are simply not apparent. For instance, EEG and similar methods of measuring brain function are characterized as continuous signals using spectral and temporal decompositions of various kinds.

Another candidate for discretized states is linguistic behaviour. There are two problems with this level of characterization: 1) language has many ‘continuous’ kinds of phenomena mixed with words (which are more obviously finite), captured by prosody, pragmatics, etc.; 2) descriptions cast at the linguistic level do not provide us with the kinds of mechanistic descriptions demanded of useful explanations in cognitive science. Many such explanations seem clearly to demand reference to ‘sub-personal,’ non-linguistic states.

In both cases, lack of apparent natural discretizations makes for lack of apparently TM-like state transitions. Hence the underlying mechanisms are unlikely to be compactly-described by TMs.

## ***5.2 Computational decompositions are not applicable to brains***

### **5.2.1 Computational architectures do not provide useful decompositions**

Computational descriptions would be useful if they imply a particular, good way to decompose the system. TM theory perhaps provides the distinction between a tape (input/output) and transition table, but this not useful for decomposing the system itself. We must turn to other possible computational architectures for such suggestions.

The most widespread computational decomposition is the von Neumann architecture. However, this architecture assumes that programs, describing the function of the system, are treated identically to the data on which such programs operate. As a result, such programs can be moved from memory to the CPU and back again. Brains do not share this flexibility. Memory and programs/function are tightly intermixed, as in a typical connectionist network. Despite some early attempts to map a von Neumann-like architecture to psychological descriptions of cognitive function (Atkinson & Shiffrin, 1968), the mapping has not proven useful. Cortex is not divisible into ‘memory’ and ‘processor’ as von Neumann architectures are.

It has been suggested that brains are parallel computers. However, parallel architectures exploit the same flexible memory usage, and so suffer from the same inability to map simply to brains.

## ***5.3 Computational descriptions do not account for variability***

Computational theory was developed in the context of ideal, non-stochastic state transitions and easily identifiable states. Digital computers are carefully engineered to respect these assumptions, and this makes their behaviour predictable and repeatable. While there are recent developments that address the effects of stochasticity on computable functions, and it has been shown that this does not affect the computational power of the system, such extensions to TMs have not informed the construction of computers. As a result, typical computational descriptions do not account for variability in the systems they describe.

When describing real physical systems, variability – in short, noise – is inescapable. Brains are no exception to this rule. The implementation independence of computational descriptions should make it unsurprising that they tend to be insensitive to implementational issues like noise.

## ***5.4 Computational descriptions do not satisfy the criteria***

Given the previous considerations, it should be clear in what sense computational descriptions do not satisfy the criteria for being good descriptions. They do not provide useful mechanistic explanations and predictions of neurobiological behaviour. This is a consequence of their not identifying the appropriate kinds of mechanisms to support intervention, which is a consequence of computational descriptions failing on the criteria

as described in sections 5.1-5.3. That is, if a description fails to 1) help decompose a system and 2) capture data through simple mechanisms (relative to a competitor), then the description cannot be used for prediction and intervention. Hence, it is not good (or, more accurately, not as good as its competitor).

I should note that the past successes of computational descriptions (e.g. ACT-R; SOAR, etc.) do not belie this point. This is because the broader claim is that models relying on computational descriptions cannot provide the unity to descriptions of cognitive phenomena that is ultimately of interest. They identify some mechanisms and interventions, but their descriptive assumptions will not capture the broad class of mechanisms and interventions of interest to cognitive scientists in general.

## **5.5 *Aside: Brains are ‘computers’ in some ways***

Notably, it is misleading to say that computational descriptions do not apply to brains, full stop. Hopefully it is clear I am not claiming this. To be clear I discuss here the ways in which brains do fall under computational descriptions, while not changing the overall conclusion that such descriptions are not good.

### **5.5.1 Brains have TM descriptions**

Given previous considerations regarding noise, it is reasonable to claim that there is some TM description of brain function. Notably, like all implementations of TMs, these will not be universal TMs (hence computationally as powerful as FSAs).

### **5.5.2 This result is uninteresting both theoretically and practically**

#### *5.5.2.1 Theoretically because of Kolmogorov*

Kolmogorov has shown two implementations of a given TM cannot be usefully considered equivalent unless they are almost identical (or unless one can assume infinite strings). As a result, identifying a TM that is implemented by the brain does not tell you how to reproduce the described function in another implementational setting.

#### *5.5.2.2 Practically because such descriptions are too easy*

As Searle has pointed out at some length, TM descriptions of physical systems are ubiquitous (he suggests Microsoft Word could be implemented by a wall). I think Searle’s point is a bit misleading: it could be really difficult to figure out how to map states from a TM description of Word to microphysical states of my wall in the appropriate way. However, when we do not know what the function is that is being computed, as in the case of the brain, we do not have any useful constraints on how to construct the TM description (i.e. we do not have a TM description already that is then mapped to the brain). As a result, it becomes extremely easy to come up with some mapping or other. We have no reason to believe such mapping is good, relevant, or in any way interesting.

### 5.5.3 Continuity is irrelevant to the goodness of quantitative descriptions

A number of authors have suggested that continuity is a feature of brains that fundamentally distinguishes it from computers (see e.g., Churchland, 1995; van Gelder, 1998; Piccinini, 2008). In fact, it has been shown that analog computers are theoretically more powerful than TMs (Siegelmann, 1995). However, this can only be shown theoretically, as it relies on complete access to the real number line. Real machines, however, do not have such access if there is any expectation of computationally irrelevant disturbance (i.e. noise, no matter how small). Consequently, there is little use spilling ink over whether or not there is some TM description of brain function – there is. However, what we are really interested in is a *good* description.

## 6 Control theoretic descriptions are good descriptions

Here, I argue that control theoretic descriptions are good descriptions of brain function at many scales. Specifically, I consider descriptions of single neurons and networks of single neurons, up to and including those responsible for linguistic behaviour.

### 6.1 *Control descriptions provide simple mappings from data to control theory states*

By far the best mechanistic descriptions we currently have of single neural cells is as non-linear electrical circuits. The circuits are naturally described by non-linear systems theory, the main mathematical tool of control theory. As a result, control theoretic states are already widely accepted as the simplest, most powerful descriptions of single neuron behaviour.

As we compose single cells into larger networks, it is useful to adopt the language of representation and computation. Eliasmith & Anderson (2003) propose the Neural Engineering Framework (NEF), a detailed theory of how neural systems can be understood in these terms. I will not review the three central principles of this approach here, but will note the following: the third principle provides a direct mapping from the single cell data typically collected by neurophysiologists to control theory. This mapping consists of a nonlinear encoding, determined directly from the data, and linear decoding that is optimal and mapped directly to the neurophysiology. This low-level neurophysiological mapping allows for prediction of single cell and aggregate data. In short, the mapping is simple between control theoretic states and many kinds of neural data.

These methods have been successfully used for a wide variety of models including the barn owl auditory system (Fischer, 2005), the rodent navigation system (Conklin & Eliasmith, 2005), escape and swimming control in zebrafish (Kuo & Eliasmith, 2005), working memory systems (Singh & Eliasmith, 2006), the translational vestibular ocular reflex in monkeys (Eliasmith, Westover, & Anderson, 2002), and context sensitive linguistic inference (Eliasmith, 2005). This variety suggests the mapping is a useful one for positing and testing neural mechanisms.

## **6.2 *Control descriptions provide a useful decomposition***

### **6.2.1 Control descriptions distinguish plants and controllers**

The central decomposition employed by control descriptions is that between a controller and a plant. While both are described by dynamical systems theory, the controller is taken to be a part of the system that varies the input to a plant, in order to achieve a desired state (provided to the controller).

### **6.2.2 Motor and perceptual systems decompose well as controllers and plants**

Peripheral neural motor systems act like controller for the body as a plant. That is, these systems determine the details of muscle contractions given higher level specifications of motor actions. More precisely, there is evidence for a hierarchy of such interactions in the motor system (Grafton & Hamilton, 2007). So, this decomposition maps in a straightforward way onto our current understanding of motor control. In addition, in closed-loop control, controllers are taken to have sensors that feedback the state of the plant, allowing the controller to be more sophisticated. This maps well onto the role of the many perceptual systems found in the brain. These systems can be naturally thought of as similarly organized (though dual) to the motor hierarchy (Todorov, 2006).

### **6.2.3 Neural systems are appropriately described as (hierarchical) directed dynamical systems**

As a result, the means of decomposing systems is useful for understanding the kinds of ‘hierarchies’ observed in the brain. That is, a nested control theoretic description of plant dynamics directed by feedback controllers, at least in that broad outline, seems appropriate to describing neural function. Furthermore, this decomposition does some justice to the massively interconnected nature of perceptual and motor systems. It is clear that we cannot yet be certain of the most appropriate decomposition of neural systems, but preliminary evidence suggests ideas from control theory may help construct just such a decomposition.

## **6.3 *Control descriptions incorporate variability***

Control theory was developed to describe physical systems. As a result, including noise, and optimizing controllers in the face of noise is a long-standing part of control theory. That is, both the analytic and synthetic aspects of control theory naturally deal with variability. This suggests such descriptions are appropriate for noisy systems like the brain. Notably, the NEF has noise as a core concern, and has been used to quantify the relationship between noise (and other variability) and neural properties in detail (Eliasmith & Anderson, 2003).

## **7 Control theoretic descriptions are the best quantitative descriptions**

This section is dedicated to a brief comparison of control theoretic descriptions with each of the other three candidates.

## 7.1 *Comparisons to computational descriptions*

It is important to emphasize that, compared to computational descriptions, control theoretic ones unify our description of phenomena of interest to cognitive scientists. For instance, working memory and navigation, are typical ‘cognitive’ phenomena. However, locomotion and reflexes are more typical ‘sensory-motor’ kinds of phenomena. Control theory applies well to all of these. And, to allay concerns that such descriptions do not apply to ‘higher’ cognitive phenomena, the BioSLIE model presented in Eliasmith (2005) is a crucial existence proof of the utility of control theoretic descriptions of linguistic, inference tasks. More generally, this model demonstrates syntactic generalization, and makes predictions regarding learning history and response times in a cognitive task (the Wason card task).

Thus, while computational descriptions are in principle poorly applicable to neuron level descriptions, control theoretic descriptions are in fact good for cognitive level descriptions.

In sum, control theoretic descriptions more effectively meet each of the criteria for good quantitative descriptions of neural systems.

These differences are in large part due to the fact that computational theory is designed to be implementation independent, whereas control theory is designed to be implementation sensitive. The physical systems that computational theory best applies to are carefully engineered. The physical systems analyzed using control theory are not. The brain, of course, falls into this latter category. Hence, it should not be surprising that control theory is in a better position to describe neural mechanisms in a manner more useful to cognitive science than the descriptions offered by computational theory.

## 7.2 *Comparisons to dynamical descriptions*

### 7.2.1 **DST dynamics is divorced from implementation**

A consequence of the DST insistence on the use of lumped parameters is precisely that such models become extremely difficult to compare to a vast majority of neural data. There is no standard way to map lumped parameters to physically manipulable parameters of the system (usually only observable behaviour is mapped to the model). As a result, there are no constraints on what might or might not be ‘lumped’ in such models. Hence no standard decomposition strategy is available.

As well, in general, such a mapping is not suggested for *specific* models either, hence the mechanisms underwriting the observed dynamics in each case is not only ad hoc, but obscure. So, despite sharing a mathematical heritage with control theory, such descriptions are not as appropriate.

### 7.2.2 **Mechanisms are abstract**

A related consequence of lumped parameters is that the mechanisms described are highly abstract. That is, to the extent there are mechanisms, there is no mapping to the internal physical states of the system, hence methods of interacting with the system are not

evident from such models. Without being able to predict the effects of interventions, the models become much less useful to the brain sciences.

### **7.3 Comparisons to statistical descriptions**

#### **7.3.1 Statistical descriptions do not provide decompositions or mechanisms**

The implementation independence of statistical descriptions has similar consequences for such descriptions as for computational ones, though for slightly different reasons. Statistical descriptions have a clear mapping to the data, as they are usually direct descriptions of the properties of the data. Indeed such a mapping can vary from experiment to experiment, making the mappings not systematic, and hence not suggesting unifying underlying mechanisms. Indeed, such descriptions are often used specifically when mechanisms are least clear.

As well, such descriptions do not provide any suggested decompositions. Statistical models typically directly adopt any decomposition assumptions from the methods used to collect the data. Hence they do not drive such decompositions, as would be desirable.

#### **7.3.2 Statistical descriptions are predictive but not explanatory**

The ‘data-focused’ nature of statistical models is both their strength and their weakness. Because statistical descriptions are most concerned with capturing regularities in the data, they are often very useful for prediction. While this is appropriate for some purposes, it does not suit what I take to be the main goal of cognitive science: *explaining* how neural systems work. As discussed in section 3.1, without identifying mechanisms, descriptions will not be explanatory, not support intervention and hence not be useful.

## **8 If we want a good description of brain function, we ought to adopt a control theoretic approach**

So, how we ought to describe computation in the brain is not as computational theory would demand. Instead, if we let pragmatic considerations drive our descriptions (as we must, otherwise we cannot choose), control theoretic descriptions are most promising for advancing our understanding of neural systems.

Recall the clarification of this conclusion: it does not rule out the other descriptions as useful. Rather, it suggests that other descriptions are essentially heuristics for stating the description in a control theoretic manner. In many cases, there are equivalent formulations of a given model in these purportedly different approaches. However, control theoretic descriptions should be primary, and hence the goal of providing good, useful descriptions of brain function.

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