2-3-21 **Lec 2**

Let's pretend there are 3 casual drivers:

Z_1: has sufficient funds to pay back loan at the time it's due?

$z_1 \in \{0,1\}$

Z_2: unforeseen emergency?

$z_2 \in \{0,1\}$

Z_3: criminal intent?

$z_3 \in \{0,1\}$

$y = t(z_1, z_2, z_3) = z_1(1-z_2)(1-z_3)$

Problems in practice?

(1) You don't know the z's b/c they are realized in the future.

(2) You may not know the function t which can be very complicated.

→

What is the next best thing since you have to make a decision now and you need a model that works now?

You obtain info. that approximates the info. in the z's and combine this information to approximate y. We denote these proxies that do this approximation the x's and we denote p to be the # of such proxies: $x_1, x_2, \dots, x_p$.

For example:

X_1: salary at the time of loan applications $\in \mathbb{R}$
X_2: missing payments previously $\in \{0, 1\}$
X_3: criminal charge in the past $\in \{0, 1\}$
$\Rightarrow p = 3$

X_j's are called features, characteristics, attributes, variables, independent variables, regressors, covariates.

What is normally done in the real world? You use the features that are available.

To learn from data, you measure the x_j's on subjects $i = 1 \dots n$.

Let $\vec{x}_i := [x_{i,1}, x_{i,2}, \dots, x_{i,p}] \in \mathcal{X}$, the input space

Subjects are also called observations, settings, records, objects, inputs.

$x_2 \in \{0,1\}$ binary variable

$x_1 \in \mathbb{R}$ continous variable

x_3 is a binary variable

} types/names of variables

Let's consider measuring x_3 differently:

$x_3 \in$ {none, infraction, misdemeanor, felony}
This is a ordinal categorical variable.

How do we make this a metric?

(1) Code it in order of severity spacing by 1:
$x_3 \in \{0,1,2,3\}$
Downside: coding is arbitrary (3) felony is worse than (1) infraction should be 7 instead of 3

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(2) Binarize / dummify this categorical variable:

$X_{3a} \in \{0,1\}$ infraction or not?
$X_{3b} \in \{0,1\}$ misdemeanor or not?
$X_{3c} \in \{0,1\}$ felony or not?

One variable became 3 variables. $\Rightarrow P=5$
I had 4 levels ($L=4$) but now I made $L-1=3$ variables. Why?
You can ~~complete~~ capture the last category (called the reference category) by setting all "dummies"/binary variables to zero.

If the variable is "nominal categorical" meaning no inherent order, you must do #2 to be able to use it in a model e.g.

$X \in \{$red, blue, green, yellow, purple, brown, ...$\}$

Next conceptual topic

Can we say that $y = f(x_1, x_2, \ldots, x_p)$?

-No! It is only approximating it at best" - Gabriel

$y = t(z_1, \ldots, z_k)$ where you don't know t or the z's.

$y \approx f(x_1, \ldots, x_p)$ δ=delta

or $y = f(x_1, \ldots, x_p) + \delta$, s.t. $\delta = t - f$

/binary What is delta? It's an error. It's an error due to... ignorance. Ignorance of the true casual drivers. It's the error due to the fact that the proxies aren't the real thing. You're missing information.

How do we decrease delta?
Increase p with more useful variables.

How do we get f?
Note that there is no "analytical solution".
The approach we use is "learning from data".
This is an "empirical approach". There are many flavors. We will concentrate on "supervised learning" from "historical data." This requires →

3 ingredients:

(1) Training Data

$\mathbb{D} = \{\langle \vec{x}_1, y_1 \rangle, \langle \vec{x}_2, y_2 \rangle, \ldots, \langle \vec{x}_n, y_n \rangle\}$

these are n historical examples of inputs/outputs.

Alternate notation:

$\mathbb{D} = \langle X, \vec{y} \rangle$ where $X = \begin{bmatrix} \leftarrow \vec{x}_1 \rightarrow \\ \leftarrow \vec{x}_2 \rightarrow \\ \vdots \\ \leftarrow \vec{x}_n \rightarrow \end{bmatrix}$ $\vec{y} = \begin{bmatrix} y_1 \\ y_2 \\ \vdots \\ y_n \end{bmatrix}$

(2) $\mathcal{H}$:= a set of candidate functions with elements h that approximate f. We need this b/c the space of all functions is too large and too ill-defined to directly find the "best one". You need to limit this space!

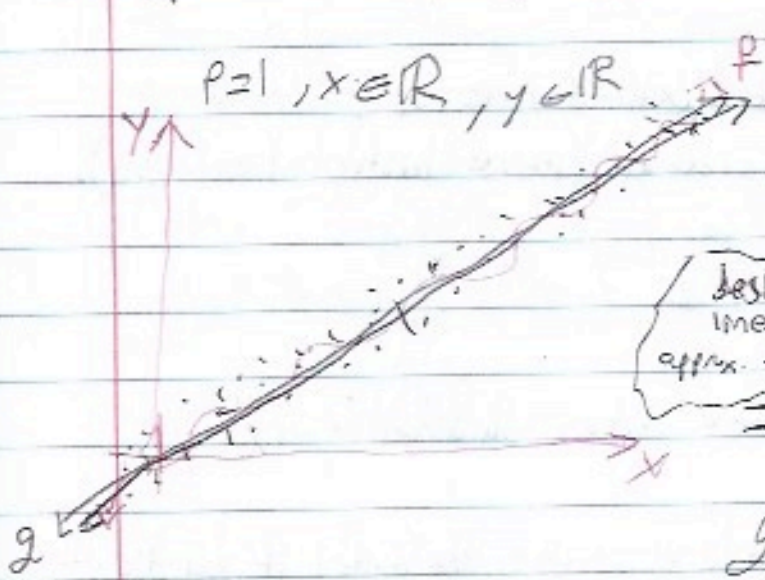
(3) We need $\mathcal{A} :=$ the algorithm that takes in $\mathbb{D}, \mathcal{H}$ and returns g, an approximation to f, so $g = \mathcal{A}(\mathbb{D}, \mathcal{H})$.

Is it true that $f \in \mathcal{H}$? No.
f is arbitrarily complicated and unknown and the set $\mathcal{H}$ contains usually simple functions that can be fit w/ $\mathcal{A}$.

outputs.

$$\begin{bmatrix} y_1 \\ y_2 \\ \vdots \\ y_n \end{bmatrix}$$

However, there is a $h^* \in \mathcal{H}$ which is the candidate model that most closely approximates f. Here is an example:



$f(x) = x + 0.1\sin($

$\mathcal{H} = \{$all linear models

best line to approx. f is h^*

~~$= \{b_0 + b_1 x$~~

$= \{b_0 + b_1 x : b_0 \in \mathbb{R}, b_1 \in \mathbb{R}\}$

$g = \mathcal{A}(\mathbb{D}, \mathcal{H})$

$y = h^*(\vec{x}) + \varepsilon$

$= h^*(\vec{x}) + (f(\vec{x}) - h^*(\vec{x})) + (y(\vec{z}) - f(\vec{x}))$

model misspecification error & (ignorance error)

ε

→

$y = \underbrace{g(\vec{x})}_{\text{model}} + \underbrace{e}_{\text{residual (the "full error" the difference b/w predicted and observed)}}$

$= g(\vec{x}) + \underbrace{h^*(\vec{x}) - g(\vec{x})}_{\text{estimation error}} + f(\vec{x}) - h^*(\vec{x}) + \underbrace{\epsilon(\vec{x}) - f(\vec{x})}_{\delta}$

ε

e

How do we decrease model misspecification error?
Expand the set of candidate functions $\mathcal{H}$ to be more complicated and thus more expressive of complex relationships.

How do we decrease estimation error?
- Increase sample size n (more historical examples). The rows in $\mathbb{D}$. i.e. [x][y] → [x] [y]

Some info on his lecture notes said "not to copy".

What is the "null model" g_0 which is the model if you didn't have any x's whatsoever?
$g_0 = \text{Mode}[\vec{y}]$
What is the simplest possible candidate space $\mathcal{H}$?
$\mathcal{H} = \{\mathbb{1}_{x \geq \theta} : \theta \in \mathbb{X}\}$ e.g. $g(x) = \mathbb{1}_{x > 600}$