

Lecture 10: Bootstrap and Kernel Methods

W

Bootstrap

- Measuring uncertainty of your model

W

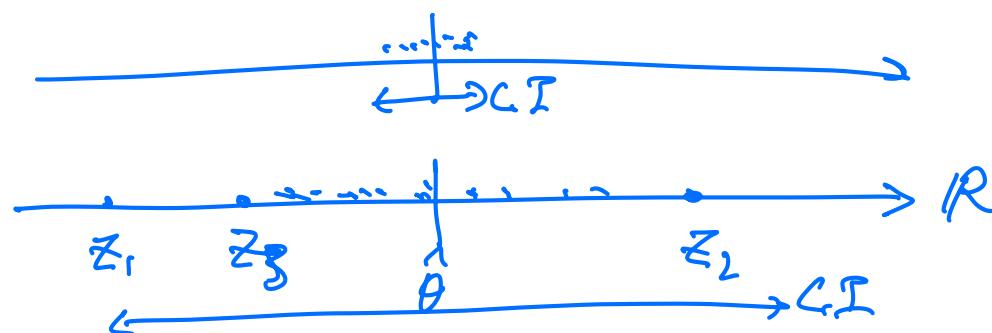
Confidence interval for statistics $\hat{\theta} = g(\mathcal{D})$

- Consider a simple problem of mean estimation given access to an oracle that gives fresh samples, and we are interested in estimating mean from n samples
- We can first collect one dataset $\mathcal{D}_n = \{z_1, \dots, z_n\} \in \mathbb{R}^n$ sampled i.i.d. from that distribution
- And compute the mean estimate using our estimator of interest, say,

$$\hat{\theta} \leftarrow g(\mathcal{D}_n) = \frac{1}{n} \sum_{i=1}^n z_i$$

empirical mean

- Furthermore, let's say we are interested in estimating how uncertain we are about this estimate. This can be done using **confidence intervals**.
- This course is not a statistics course, so we do not go into a great detail on confidence interval. We will only be using it to learn **bootstrapping**.



- We have a mean estimate using our estimator of interest, say,

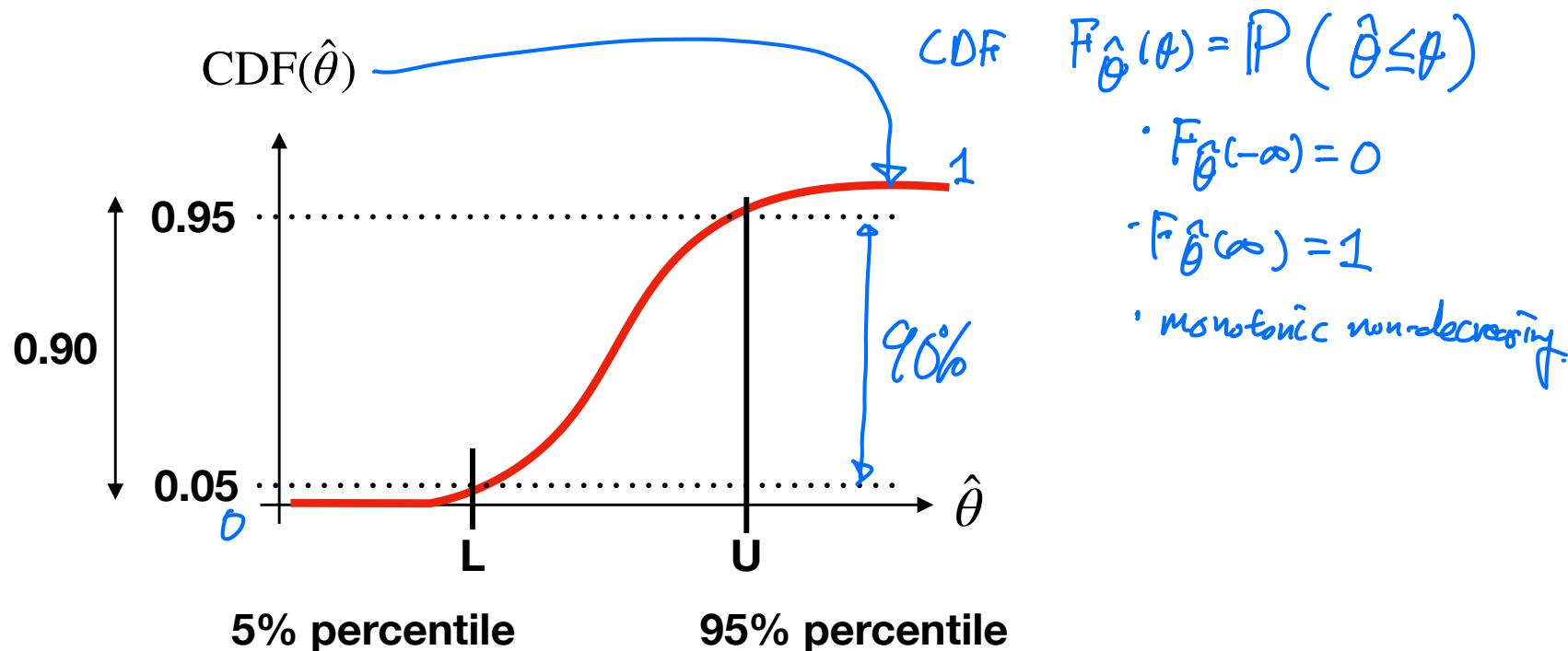
$$\hat{\theta} \leftarrow g(\mathcal{D}_n) = \frac{1}{n} \sum_{i=1}^n z_i$$

and an oracle sampler from some distribution P_Z .

- If we know the distribution of our estimate $\hat{\theta}$, then one would output a, for example, 90% confidence interval of

$$CI = [L, U]$$

- The main idea is to ensure that the actual mean, say θ^* , of the distribution P_Z falls in the CI with probability at least 90%.



Confidence interval for statistics $\hat{\theta} = g(\mathcal{D})$

- We have a mean estimate using our estimator of interest, say,

$$\hat{\theta} \leftarrow g(\mathcal{D}_n) = \frac{1}{n} \sum_{i=1}^n z_i$$

and an oracle sampler from some distribution P_Z .

- If we know the distribution of our estimate $\hat{\theta}$, then one would output a, for example, 90% confidence interval of

$$CI = [L, U]$$

- The main idea is to ensure that the actual mean, say θ^* , of the distribution P_Z falls in the CI with probability at least 90%.
- The problem is that we typically do not know the distribution of $\hat{\theta}$, so what can we do?
 - This is easy if we have an oracle and can keep sampling new datasets \mathcal{D}_n so that we can get multiple “samples” of $\hat{\theta}$ to estimate its distribution.

\uparrow
 $g(\mathcal{D}_n)$

Confidence interval with oracle access to sampler

- “sample” many fresh datasets $\{\mathcal{D}_n^{(1)}, \dots, \mathcal{D}_n^{(B)}\}$, each of size n
- compute estimates $\{\hat{\theta}^{(1)} = g(\mathcal{D}_n^{(1)}) \dots, \hat{\theta}^{(B)} = g(\mathcal{D}_n^{(B)})\}$ for each dataset

gives something that is impossible in real world.

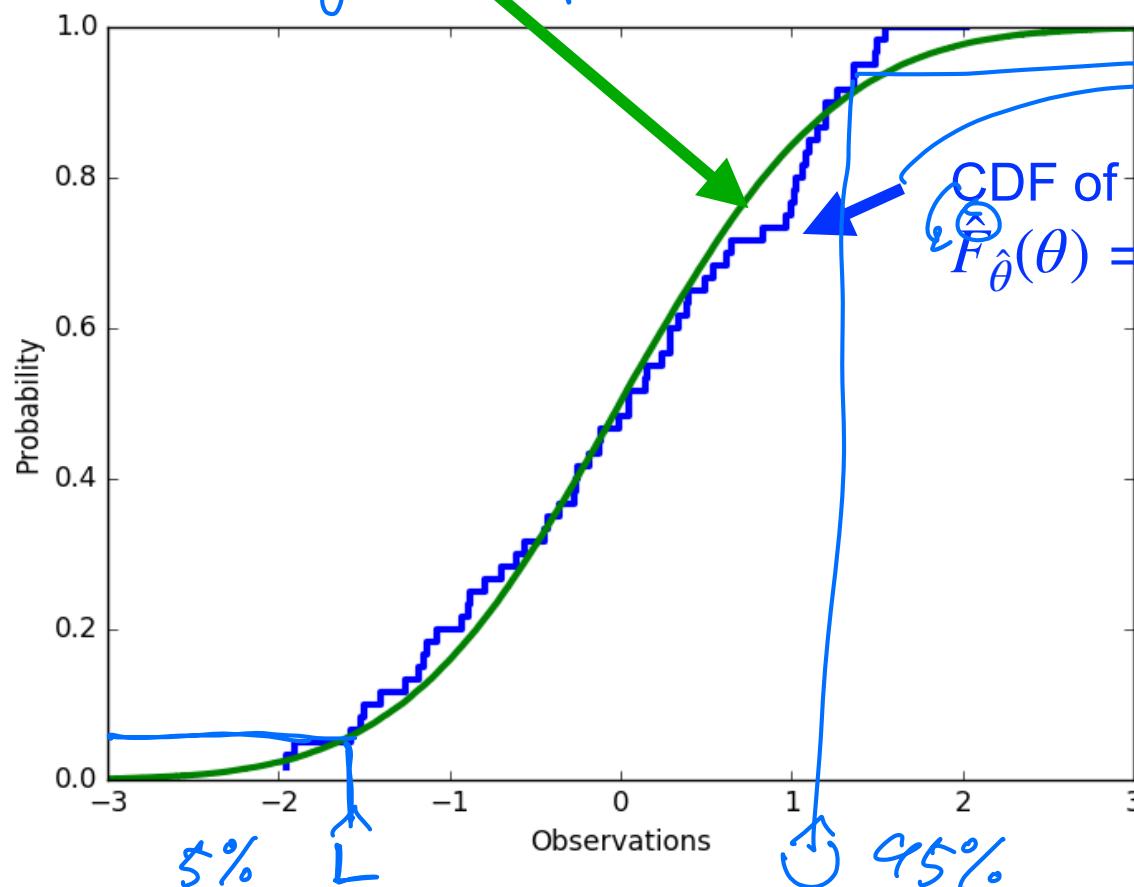
↑ Total? Bn

B “samples” of $\hat{\theta}$

CDF of an unknown True distribution

$$F_{\hat{\theta}}(\theta) = P_{\mathcal{D}}(g(\mathcal{D}_n) \leq \theta)$$

population CDF



Set-up for regression/classification

We have a dataset of n samples drawn i.i.d. with (CDF) F_Z

$$\mathcal{D}_n = \{z_1, \dots, z_n\} \sim F_Z$$

We compute a *statistic* of the data to get $g(\mathcal{D})$

Goal: Estimate uncertainty around $g(\mathcal{D})$.

In other words, what's the distribution of $g(\mathcal{D})$ over different random samples of \mathcal{D} ?

Q: what is the $g(\mathcal{D})$ statistic
we care about in regression?

Set-up for regression/classification

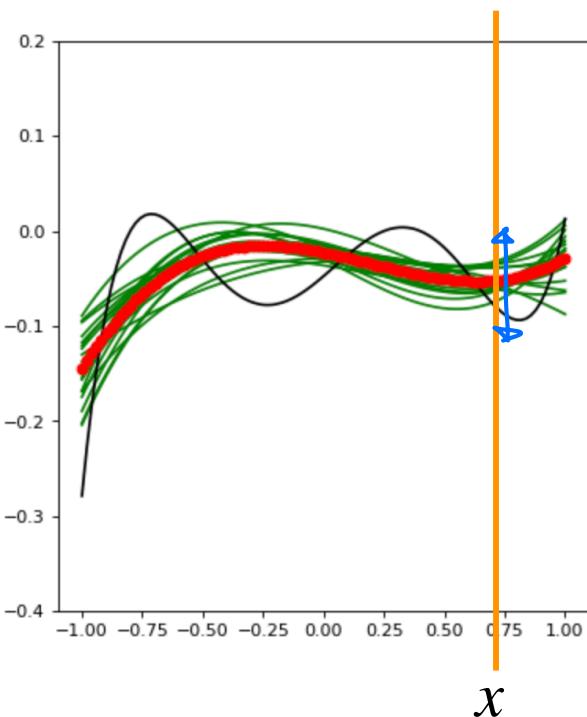
We have a dataset of n samples drawn i.i.d. with (CDF) F_Z

$$\mathcal{D} = \{z_1, \dots, z_n\} \sim F_Z$$

We compute a *statistic* of the data to get $g(\mathcal{D})$

Goal: Estimate uncertainty around $g(\mathcal{D})$.

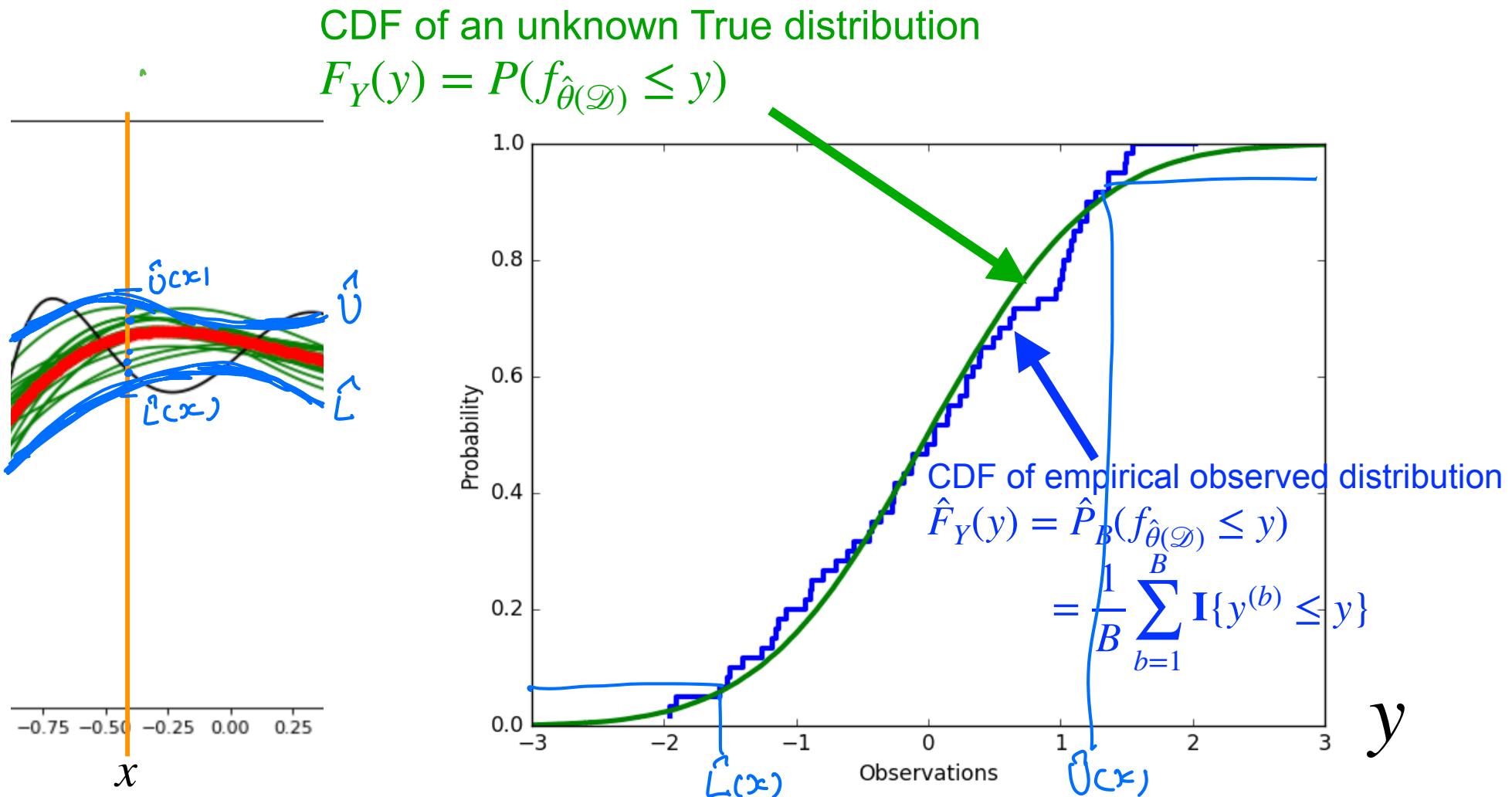
In other words, what's the distribution of $g(\mathcal{D})$ over different random samples of \mathcal{D} ?



For example, in the example of regression, we might care about $g(\mathcal{D}) = f_{\hat{\theta}(\mathcal{D})}(x)$, :*prediction*, where $\hat{\theta}(\mathcal{D})$ is the model parameter trained on the train-set \mathcal{D} , and $f_{\hat{\theta}(\mathcal{D})}(x)$ is our prediction for input x .

Confidence interval with oracle access to sampler

- “sample” many fresh datasets $\{\mathcal{D}_n^{(1)}, \dots, \mathcal{D}_n^{(B)}\}$, each of size n
- train models $\{\hat{\theta}^{(1)}, \dots, \hat{\theta}^{(B)}\}$ for each dataset
- compute the prediction $\{y^{(1)} = f_{\hat{\theta}(\mathcal{D}^{(1)})}(x), \dots, y^{(B)} = f_{\hat{\theta}(\mathcal{D}^{(B)})}(x)\}$



Bootstrapping: doing something seemingly impossible



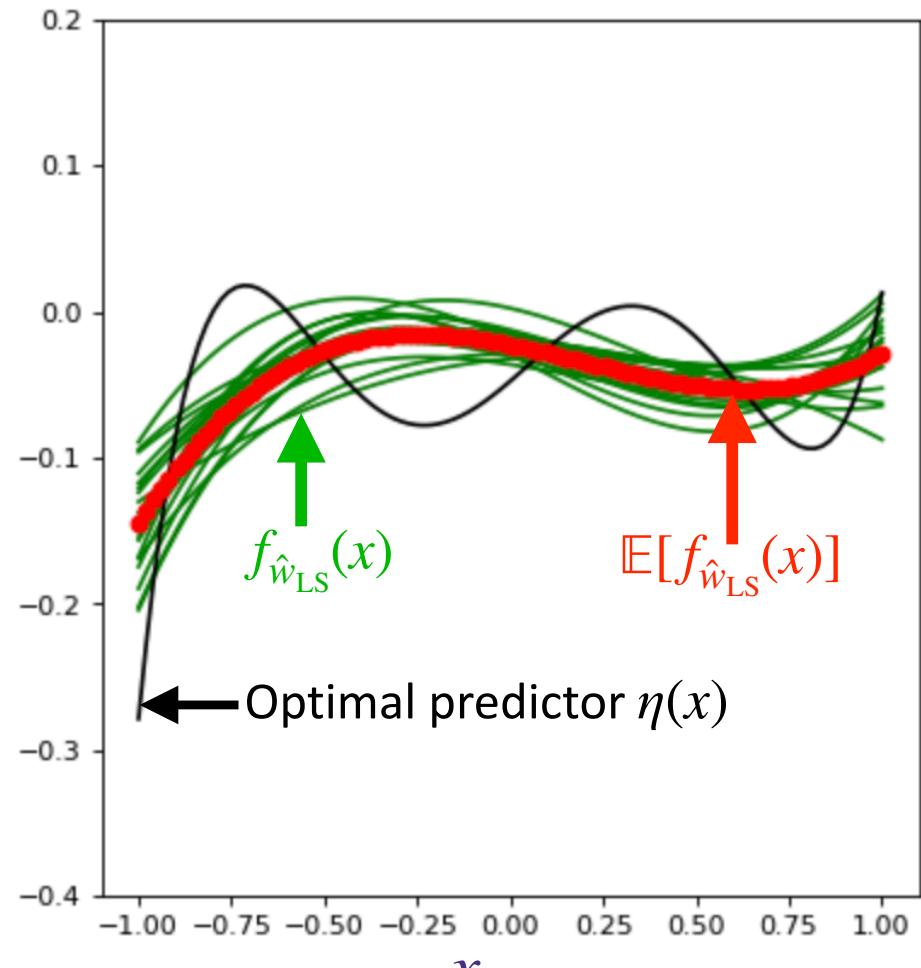
- pull oneself up by one's bootstraps — improve one's position by one's own efforts without help from others.
- In our context: A general method of calculating uncertainty estimates without any additional data. (Efron, 1979)

Bootstrapping: doing something seemingly impossible

to pull oneself up by one's bootstraps



Remember bias-variance trade-off?



x
current train error = 0.0036791644380554187
current test error = 0.0037962529988410953

It is seemingly impossible to compute **Variance**, for example, with a single dataset.

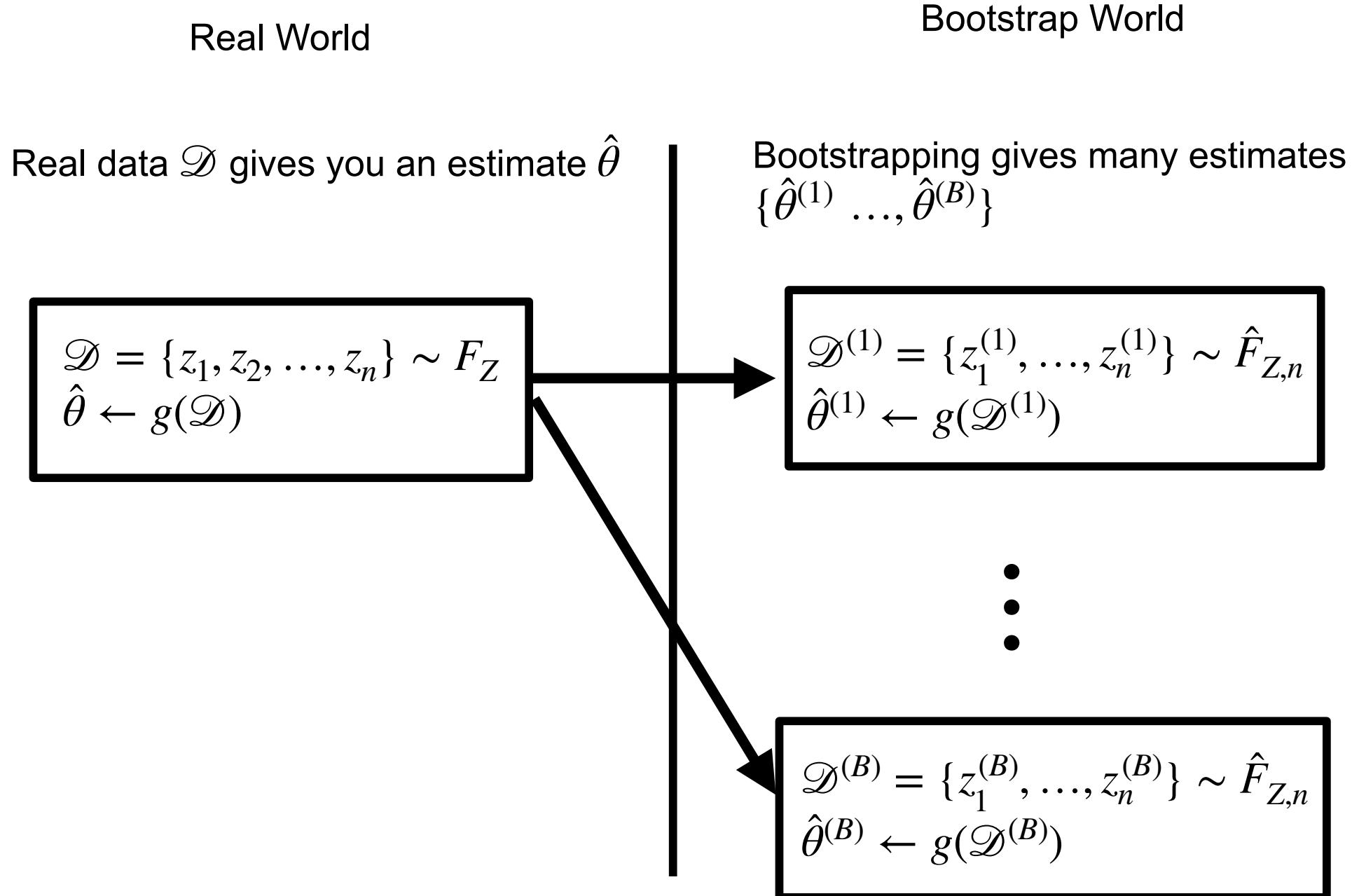
Bootstrap: Key idea

- Goal: Estimate uncertainty around an estimate $\hat{\theta} = g(\mathcal{D})$ from a dataset $\mathcal{D} = \{z_1, z_2, \dots, z_n\} \sim F_Z$
- This would be easy if we had multiple datasets \mathcal{D} drawn fresh from F_Z
- Idea: pretend that we have fresh draws from F_Z by **sampling with replacement** from \mathcal{D}
- Concretely,
 - for $b = 1, \dots, B$,

Bootstrap: Key idea

- Goal: Estimate uncertainty around an estimate $\hat{\theta} = g(\mathcal{D})$ from a dataset $\mathcal{D} = \{z_1, z_2, \dots, z_n\} \sim F_Z$
 - This would be easy if we had multiple datasets \mathcal{D} drawn fresh from F_Z
 - Idea: pretend that we have fresh draws from F_Z by **sampling with replacement** from \mathcal{D}
 - Concretely,
 - for $b = 1, \dots, B$,
 - draw n samples with replacement from \mathcal{D} , and call them $\mathcal{D}^{(b)} = \{z_1^{(b)}, \dots, z_n^{(b)}\} \sim \hat{F}_{Z,n}$
 - compute the estimate $\hat{\theta}^{(b)} \leftarrow g(\mathcal{D}^{(b)})$
 - use $\{\hat{\theta}^{(b)}\}_{b=1}^B$ to compute the confidence interval
- $\in \{1, \dots, B\}$
 $\in \{1, \dots, n\}$

Bootstrap: step 1: sampling with replacement

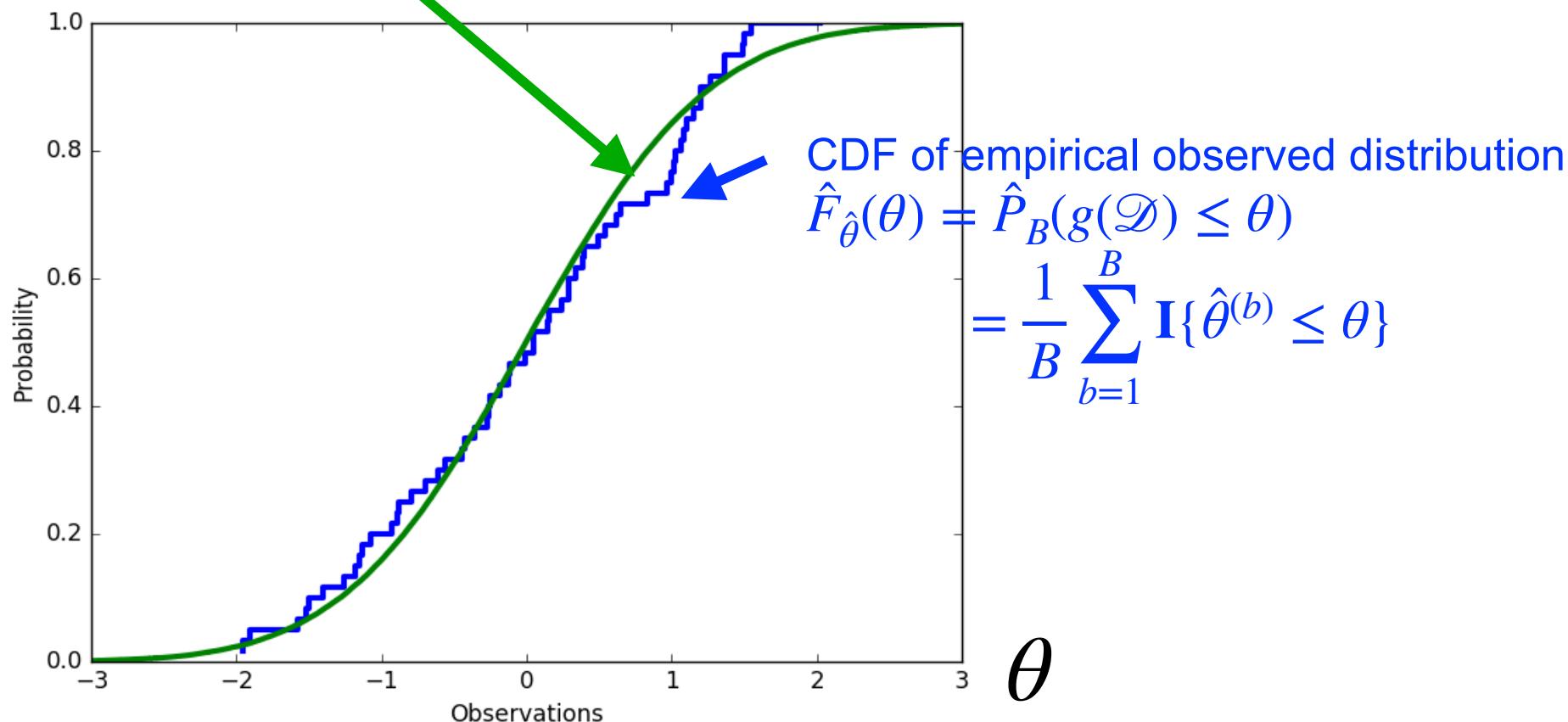


Bootstrap: step 2: confidence interval

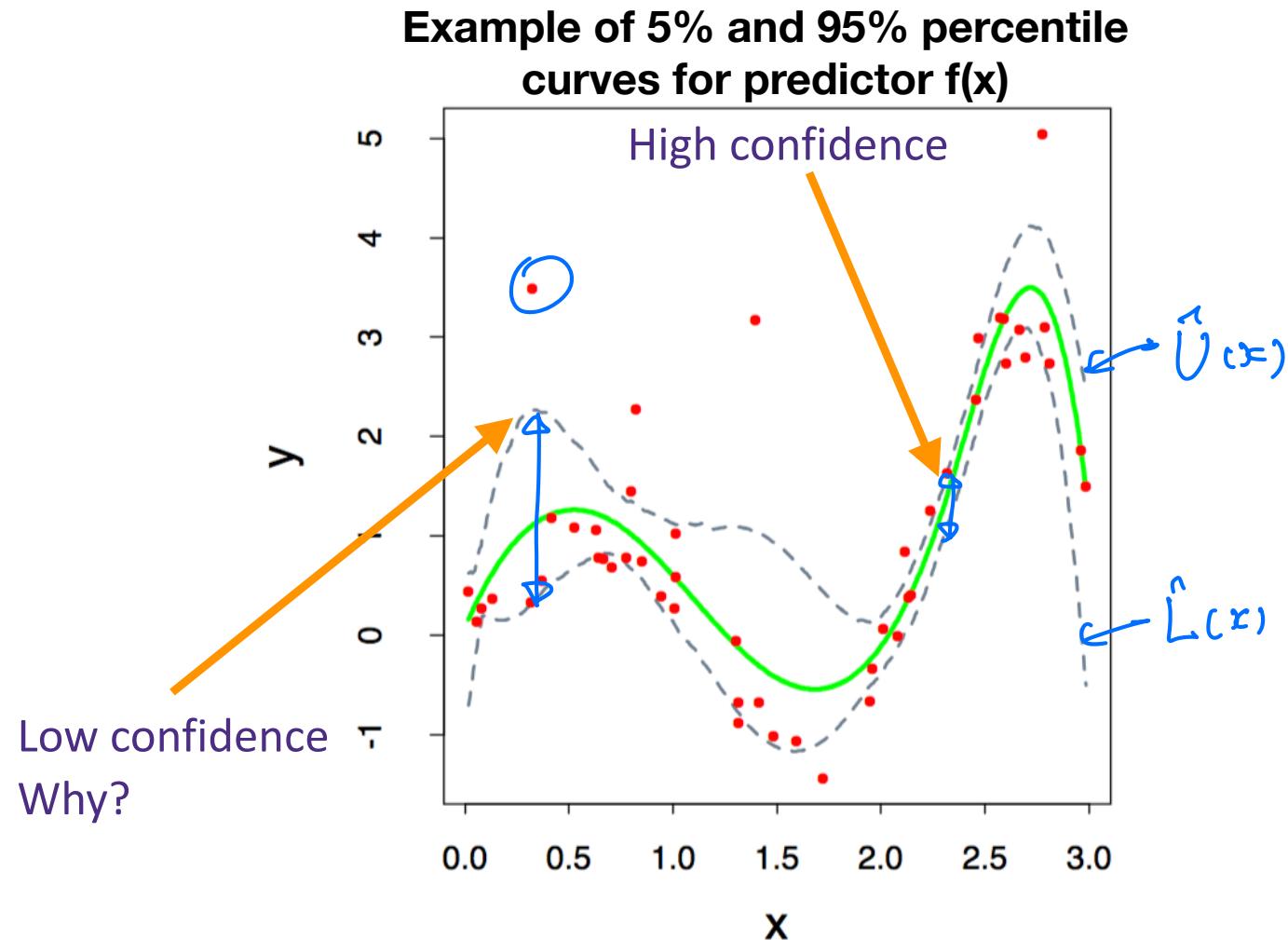
- Bootstrap “sample” many fresh datasets $\{\mathcal{D}^{(1)}, \dots, \mathcal{D}^{(B)}\}$, each of size n
- compute estimates $\{\hat{\theta}^{(1)} = g(\mathcal{D}^{(1)}) \dots, \hat{\theta}^{(B)} = g(\mathcal{D}^{(B)})\}$ for each dataset

CDF of an unknown True distribution

$$F_{\hat{\theta}}(\theta) = P_{\mathcal{D}}(g(\mathcal{D}) \leq \theta)$$



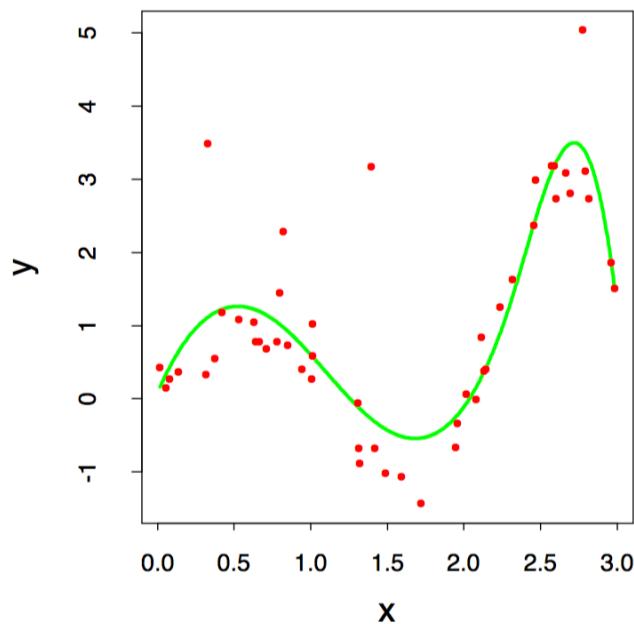
Example for 1-d regression



The green line is $f_D(x)$, and the black dashed lines are the 5% and 95% percentiles at each x

bootstrap

training a single predictor

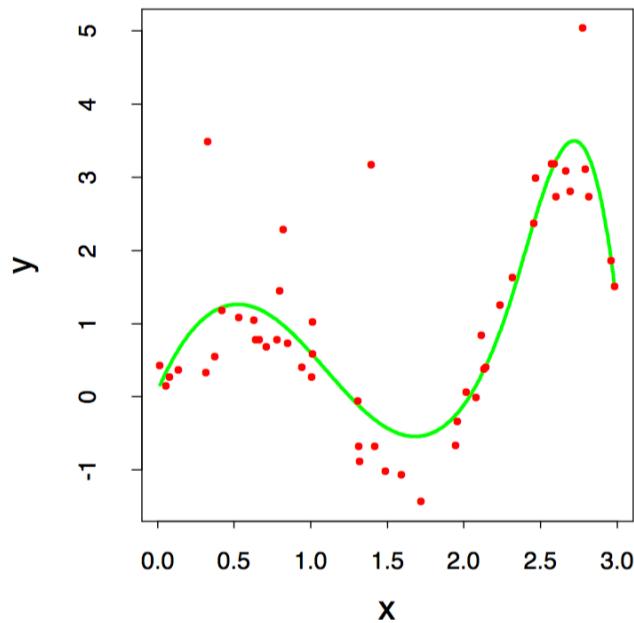


multiple bootstrapped predictors

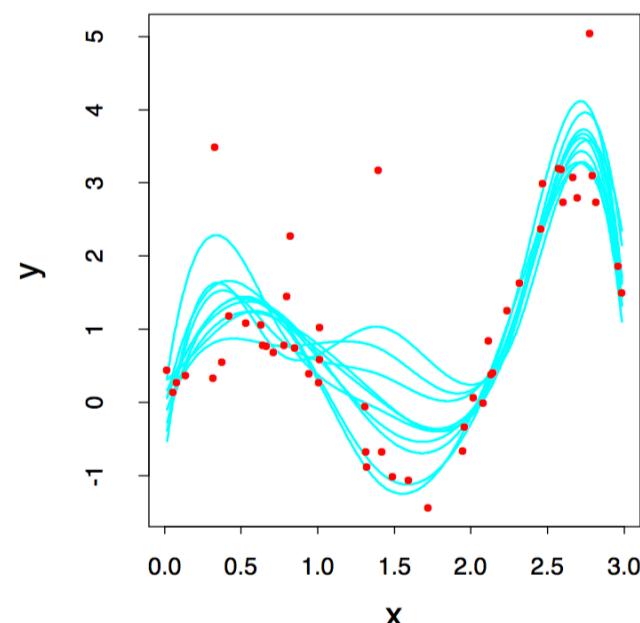
90% confidence interval

bootstrap

training a single predictor



multiple bootstrapped predictors

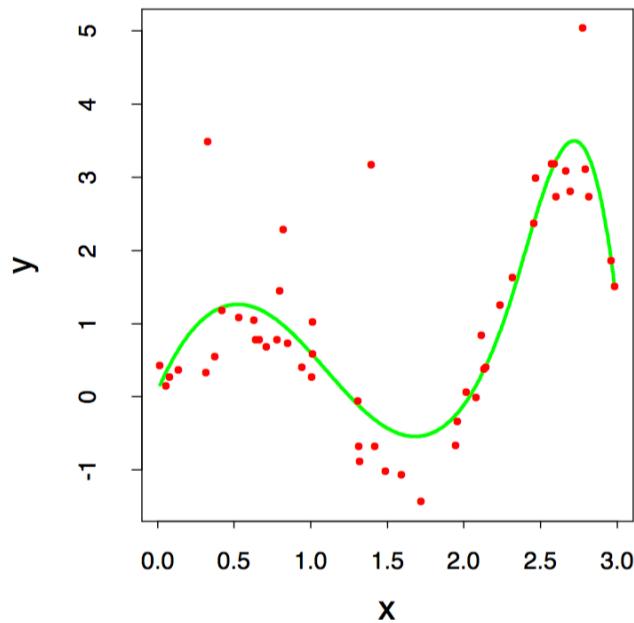


90% confidence interval

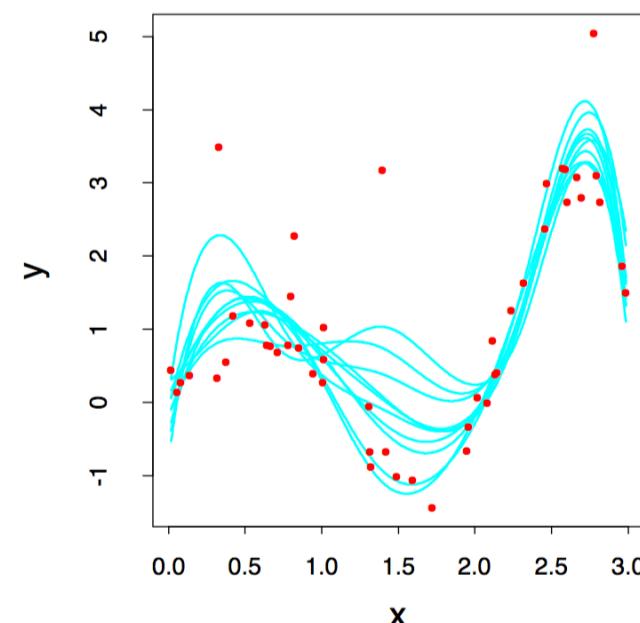


bootstrap

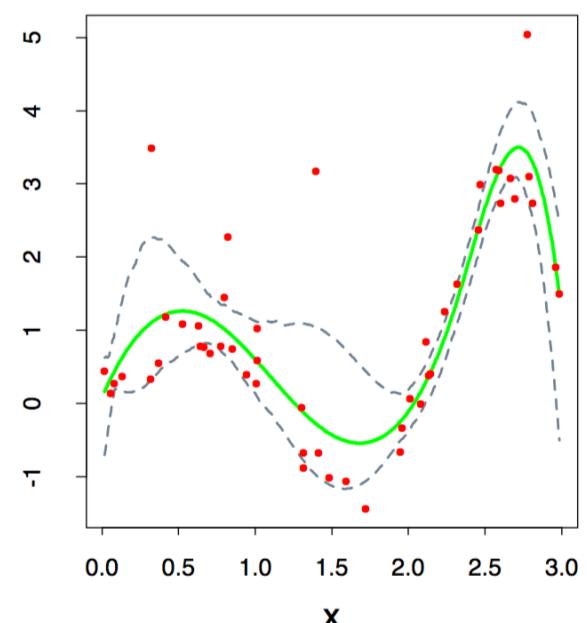
training a single predictor



multiple bootstrapped predictors



90% confidence interval



Takeaways

Advantages:

- Very simple to use and generally applicable – build a confidence interval around anything
- Appears to give meaningful results even when the amount of data is very small
- Very strong asymptotic theory (as number of examples goes to infinity)

Disadvantages:

- Very few meaningful finite-sample guarantees
- Potentially computationally intensive
- Reliability hinges on test statistic and rate of convergence of empirical CDF to true CDF, which is unknown
- Poor performance on “extreme statistics” (e.g., the max)

Kernel methods

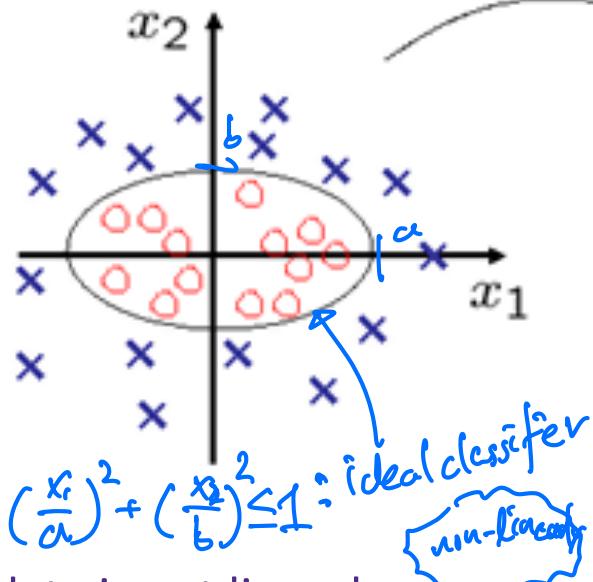
parameters ↑
to tune
+ complexity.

W

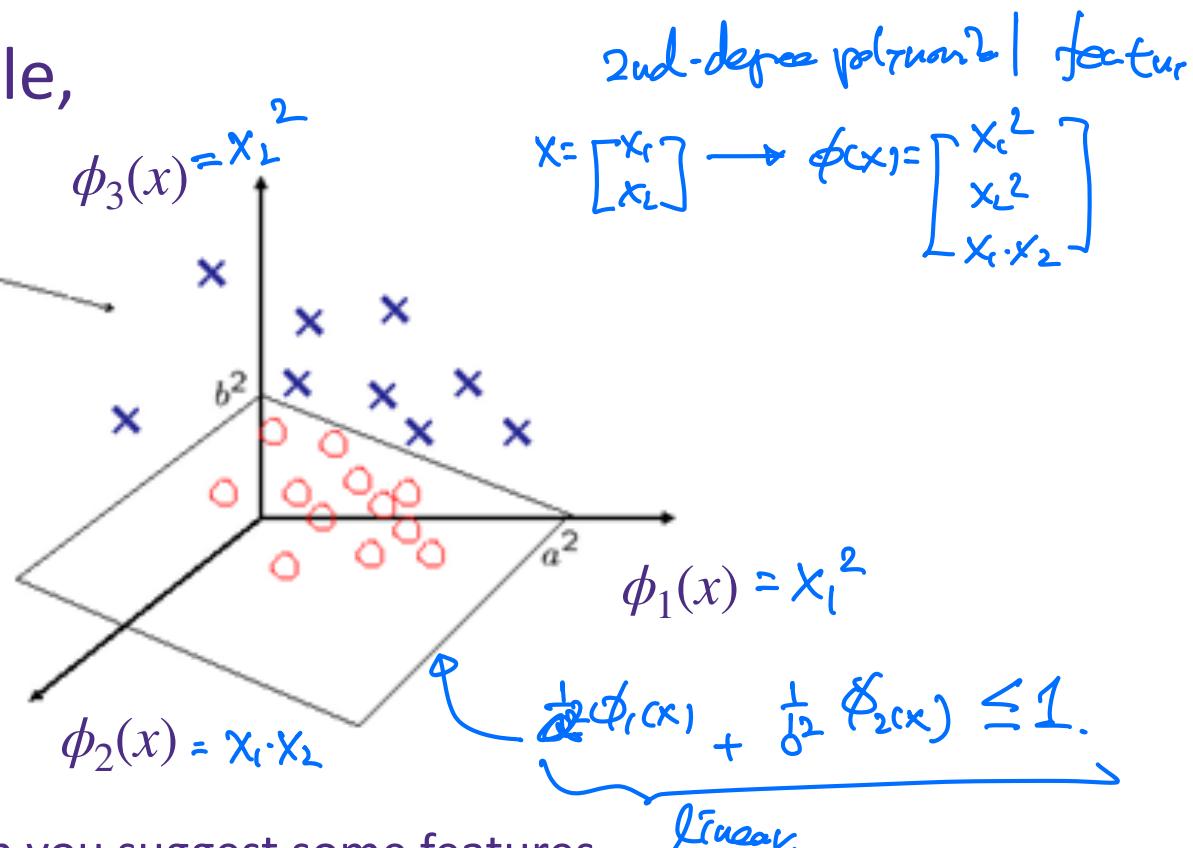
What if the data is not linearly separable?

- Use features, for example,

$$x = (x_1, x_2) \in \mathbb{R}^2$$



This data is not linearly
separable

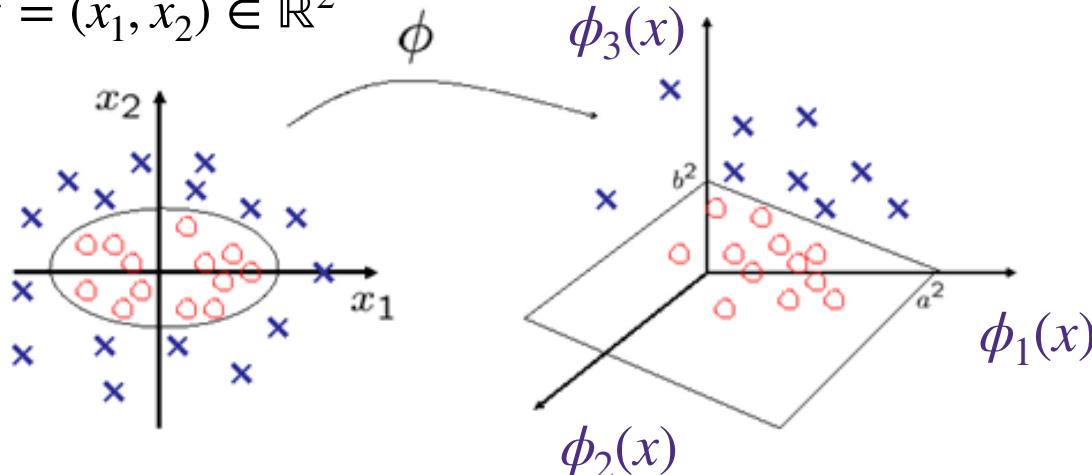


Can you suggest some features
 $\phi_1(x_1, x_2), \phi_2(x_1, x_2), \phi_3(x_1, x_2)$ such that this data is
linearly separable in this 3-dimensional space?

What if the data is not linearly separable?

- Use features, for example,

$$x = (x_1, x_2) \in \mathbb{R}^2$$



This data is not linearly separable

Can you suggest some features $\phi_1(x_1, x_2), \phi_2(x_1, x_2), \phi_3(x_1, x_2)$ such that this data is linearly separable in this 3-dimensional space?

- Generally, in high dimensional feature space, it is easier to linearly separate different classes
- However, it is hard to know which feature map will work for given data
- So the rule of thumb is to use high-dimensional features and hope that the algorithm will automatically pick the right set of features
- What is wrong with this approach? → *com punfeat*

Creating Features

- Feature mapping $\phi : \mathbb{R}^d \rightarrow \mathbb{R}^p$ maps original data into a rich and high-dimensional feature space (usually $d \ll p$)

For example, in $d=1$, one can use

$$\phi(x) = \begin{bmatrix} \phi_1(x) \\ \phi_2(x) \\ \vdots \\ \phi_k(x) \end{bmatrix} = \begin{bmatrix} x \\ x^2 \\ \vdots \\ x^k \end{bmatrix}$$

For example, for $d>1$, one can generate vectors $\{u_j\}_{j=1}^p \subset \mathbb{R}^d$

and define features:

$$\phi_j(x) = \cos(u_j^T x) \rightarrow$$

$$\phi_j(x) = (u_j^T x)^2 \rightarrow \text{poly}$$

$$\phi_j(x) = \frac{1}{1 + \exp(u_j^T x)} \rightarrow \text{logistic}$$

↑
non-linear features

$$\left[\begin{array}{c} \cos(u_1^T x) \\ \cos(u_2^T x) \\ \vdots \\ \cos(u_p^T x) \end{array} \right] \subset \mathbb{R}^p$$

Creating Features

- Feature mapping $\phi : \mathbb{R}^d \rightarrow \mathbb{R}^p$ maps original data into a rich and high-dimensional feature space (usually $d \ll p$)

For example, in $d=1$, one can use

$$\phi(x) = \begin{bmatrix} \phi_1(x) \\ \phi_2(x) \\ \vdots \\ \phi_k(x) \end{bmatrix} = \begin{bmatrix} x \\ x^2 \\ \vdots \\ x^k \end{bmatrix}$$

For example, for $d>1$, one can generate vectors $\{u_j\}_{j=1}^p \subset \mathbb{R}^d$

and define features:

$$\phi_j(x) = \cos(u_j^T x)$$

$$\phi_j(x) = (u_j^T x)^2$$

$$\phi_j(x) = \frac{1}{1 + \exp(u_j^T x)}$$

- Feature space can get really large really quickly!
- How many coefficients/parameters are there for degree- k polynomials for $x = (x_1, \dots, x_d) \in \mathbb{R}^d$? $\Theta(d^k)$
- At a first glance, it seems inevitable that we need memory (to store the features $\{\phi(x_i) \in \mathbb{R}^p\}_{i=1}^n$) and run-time that increases with p where $d < n \ll p$

How do we deal with high-dimensional lifts/data?

A fundamental trick in ML: use kernels

features $\xrightarrow{\text{lift}}$ raw data
info lift-dim.

A function $K : \mathbb{R}^d \times \mathbb{R}^d \rightarrow \mathbb{R}$ is a **kernel** for a map $\phi(\cdot)$ if $K(x, x') \triangleq \phi(x)^T \phi(x') = \phi(x) \cdot \phi(x') = \langle \phi(x), \phi(x') \rangle$

This notation is for dot product (which is the same as inner product)
 $= \text{inner product.}$

- Main idea: computing inner products can be much more efficient than explicitly commuting the (very high-dimensional) features

$$\phi(x_1, \phi(x_r))$$

How do we deal with high-dimensional lifts/data?

A fundamental trick in ML: use kernels

A function $K : \mathbb{R}^d \times \mathbb{R}^d \rightarrow \mathbb{R}$ is a **kernel** for a map $\phi(\cdot)$ if $K(x, x') \triangleq \phi(x)^T \phi(x') = \phi(x) \cdot \phi(x') = \langle \phi(x), \phi(x') \rangle$

This notation is for dot product (which is the same as inner product)

- So, if we can represent our
 - training algorithms and
 - decision rules for prediction
- as functions of dot products of feature maps (i.e. $\{\phi(x) \cdot \phi(x')\}$) and if we can find a kernel for our feature map such that

$$K(x, x') = \phi(x)^T \phi(x')$$

then we can avoid explicitly computing and storing (high-dimensional) $\{\phi(x_i)\}_{i=1}^n$ and instead only work with the kernel matrix of the training data
 $\{K(x_i, x_j)\}_{i,j \in \{1, \dots, n\}}$ [Homework 3 Problem A2 tests this skill]

Kernels are much more efficient to compute than features

- As illustrating examples, consider polynomial features of degree exactly k

- $\phi(x) = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$ for $k = 1$ and $d = 2$, then $K(x, x') = x_1 x'_1 + x_2 x'_2$

- $\phi(x) = \begin{bmatrix} x_1^2 \\ x_2^2 \\ x_1 x_2 \\ x_2 x_1 \end{bmatrix}$ for $k = 2$ and $d = 2$, then $K(x, x') = (x^T x')^2$
 $= x_1^2 x'^2 + x_2^2 x'^2 + x_1 x_2 x'_1 x'_1 + x_2 x_1 x'_2 x'_1$
 $= \underbrace{(x_1 x'_1 + x_2 x'_2)^2}_{O(d)} *$
O(d²) compute

Kernels are much more efficient to compute than features

- As illustrating examples, consider polynomial features of degree exactly k

- $\phi(x) = \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$ for $k = 1$ and $d = 2$, then $K(x, x') = x_1x'_1 + x_2x'_2$

- $\phi(x) = \begin{bmatrix} x_1^2 \\ x_2^2 \\ x_1x_2 \\ x_2x_1 \end{bmatrix}$ for $k = 2$ and $d = 2$, then $K(x, x') = (x^T x')^2$

- Note that for a data point x_i , **explicitly** computing the feature $\phi(x_i)$ takes memory/time $p = d^k \rightarrow d^{K,n}$
- For a data point x_i , if we can make predictions by only computing the kernel, then computing $\{K(x_i, x_j)\}_{j=1}^n$ takes memory/time dn
 - The features are **implicit** and accessed only via kernels, making it efficient

Examples of popular Kernels

- Polynomials of degree exactly k

$$K(x, x') = (x^T x')^k$$

$$\Phi(x) = \begin{bmatrix} x_1^K \\ x_2^K \\ \vdots \\ x_d^K \\ 1 \end{bmatrix}$$

- Polynomials of degree up to k

$$K(x, x') = (1 + x^T x')^k$$

- Gaussian (squared exponential) kernel
(a.k.a RBF kernel for Radial Basis Function)

$$K(x, x') = \exp\left(-\frac{\|x - x'\|_2^2}{2\sigma^2}\right)$$

- Sigmoid

$$K(x, x') = \tanh(\gamma x^T x' + r)$$

- All these kernels are efficient to compute, but the corresponding features are in infinite dimensions

infinite

Example: feature vs. kernel

- Ridge regression with feature map $\phi(\cdot) \in \mathbb{R}^p$
 - Solve for $\widehat{w} = \arg \min_{w \in \mathbb{R}^p} \frac{1}{2} \sum_{i=1}^n (y_i - w^T \phi(x_i))^2 + \lambda \frac{1}{2} \|w\|_2^2$
 - Slow when $p \gg d$
- For now, suppose we are solving this using gradient descent with
 - $w_0 = 0$ and
 - $w_{t+1} \leftarrow w_t + \eta \sum_{i=1}^n \phi(x_i) (y_i - w_t^T \phi(x_i)) - \eta \lambda w_t$ $= (1-\eta\lambda)w_t + \eta \sum_{i=1}^n \phi(x_i) (y_i - w_t^T \phi(x_i))$
 - Claim: For any t , w_t can be represented as $w_t = \sum_{i=1}^n \alpha_i \phi(x_i)$ for some n -dimensional parameter $\alpha = (\alpha_1, \dots, \alpha_n)$
 - Prediction $\hat{y}_{\text{new}} = \hat{w}^T \phi(x_{\text{new}}) = \sum_{i=1}^n \hat{\alpha}_i \phi(x_i)^T \phi(x_{\text{new}})$

Kernel ridge regression

$$K \triangleq \phi(x) \phi(x)^T$$

- Ridge regression with feature map $\phi(\cdot) \in \mathbb{R}^p$

$$\hat{w} = \arg \min_{w \in \mathbb{R}^p} \frac{1}{2} \|y - \phi(X)w\|_2^2 + \lambda \frac{1}{2} \|w\|_2^2$$

- $w = \sum_{i=1}^n \alpha_i \phi(x_i) = \phi(X)^T \alpha$

$$w = w_1, \dots, w_p$$

with now an n -dimensional parameter $\alpha = (\alpha_1, \dots, \alpha_n)$, instead of p

- Let $K \in \mathbb{R}^{n \times n}$ be the kernel matrix, where $K_{i,j} = \phi(x_i)^T \phi(x_j)$
- The new objective is $\hat{\alpha} = \arg \min_{\alpha \in \mathbb{R}^n} \frac{1}{2} \|y - \underbrace{\phi(x) \cdot \phi(x)^T \alpha}_K\|_2^2 + \lambda \frac{1}{2} \alpha^T \underbrace{\phi(x) \phi(x)^T \alpha}_K \alpha$

$$\nabla_{\alpha} = -K \cdot (y - K\alpha) + \lambda K \alpha = 0$$

$$(K + \lambda I) \alpha = y$$

Thus, $\hat{\alpha}_{\text{kernel}} = (K + \lambda I_{n \times n})^{-1} y$

- Prediction $\hat{y}_{\text{new}} = \hat{w}^T \phi(x_{\text{new}}) = \sum_{i=1}^n \alpha_i \phi(x_i)^T \phi(x_{\text{new}}) = \sum_{i=1}^n K(x_i, x_{\text{new}}) \alpha$

Kernel regression

- This holds for more general class of algorithms other than GD:

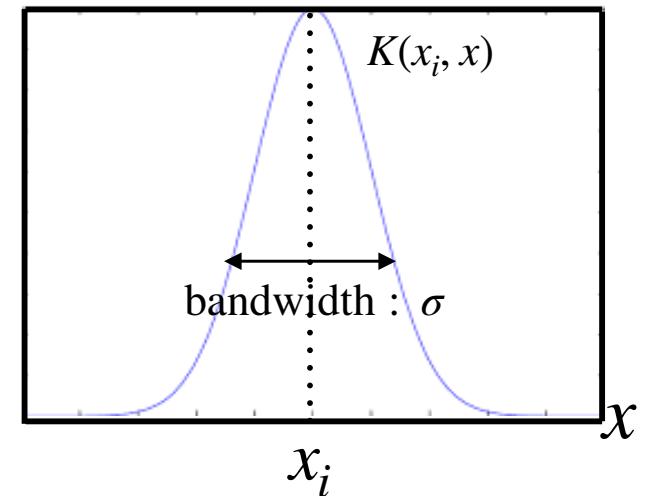
$$w = \sum_{i=1}^n \alpha_i \phi(x_i) = \phi(X)^T \alpha$$

with now an n -dimensional parameter $\alpha = (\alpha_1, \dots, \alpha_n)$, instead of p

- Kernel method is not limited to linear Ridge regression, but also applies to a broad class of methods including the kernel logistic regression

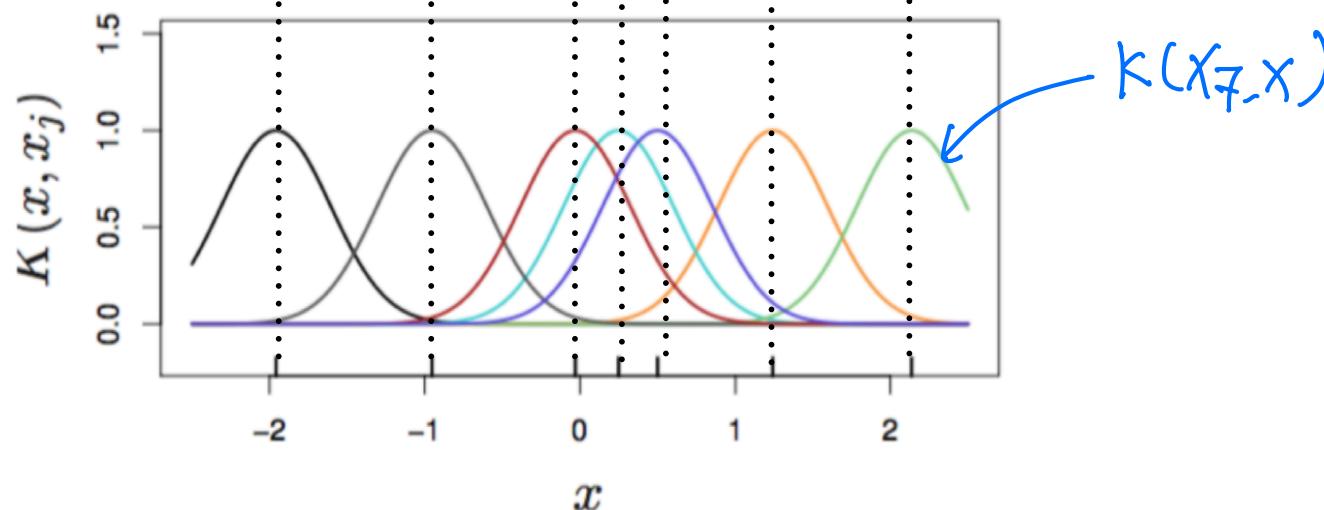
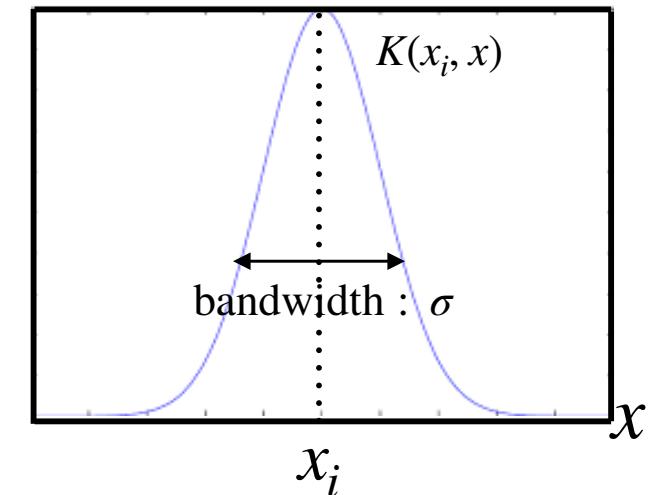
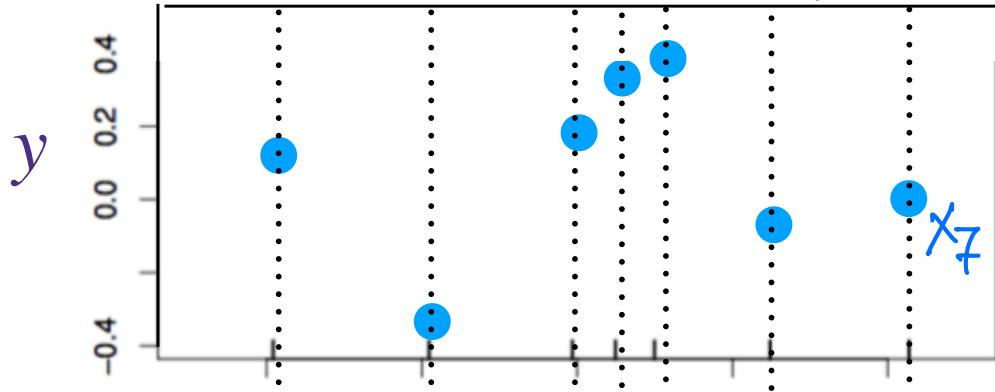
[Homework 3 Problem A3 implements kernel regression for polynomial kernel and RBF kernel]

$$\text{RBF kernel } k(x_i, x) = \exp\left\{-\frac{\|x_i - x\|_2^2}{2\sigma^2}\right\}$$



RBF kernel $k(x_i, x) = \exp\left\{-\frac{\|x_i - x\|_2^2}{2\sigma^2}\right\}$

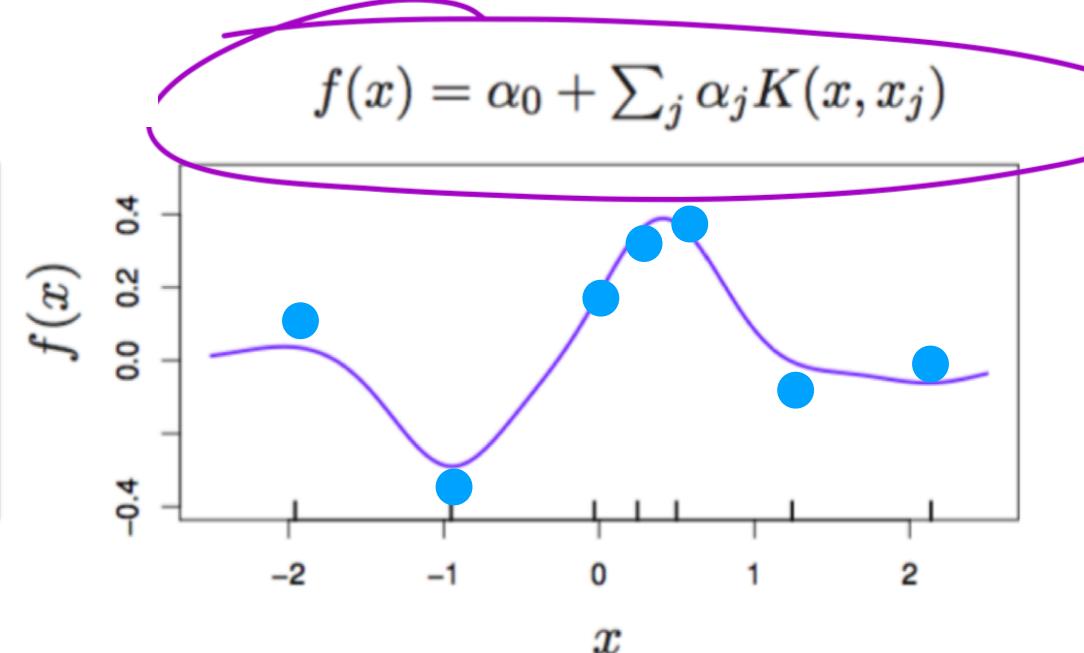
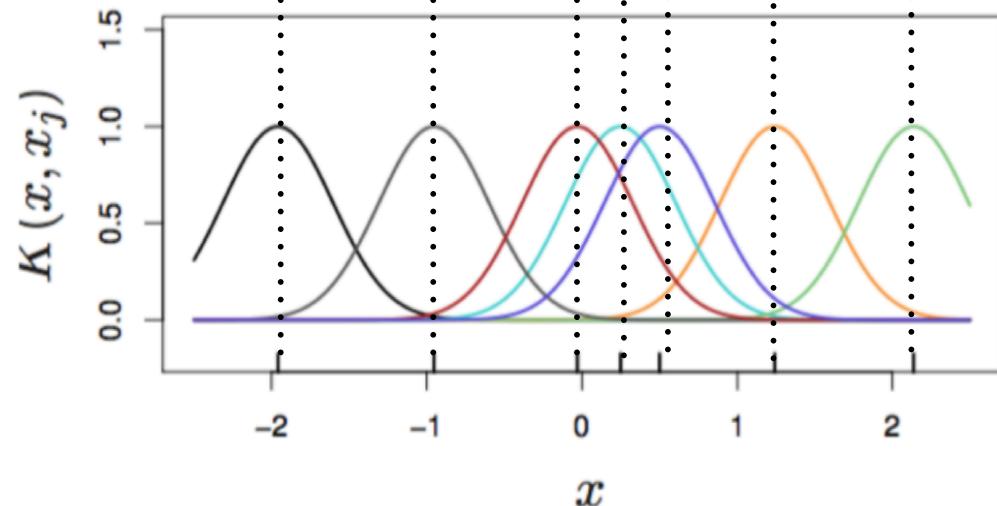
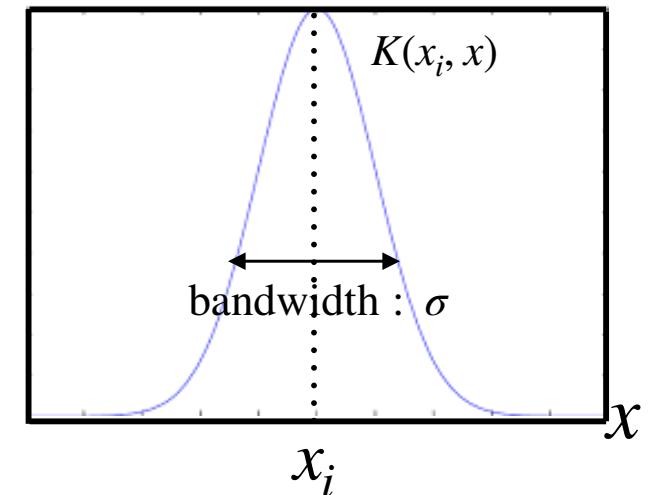
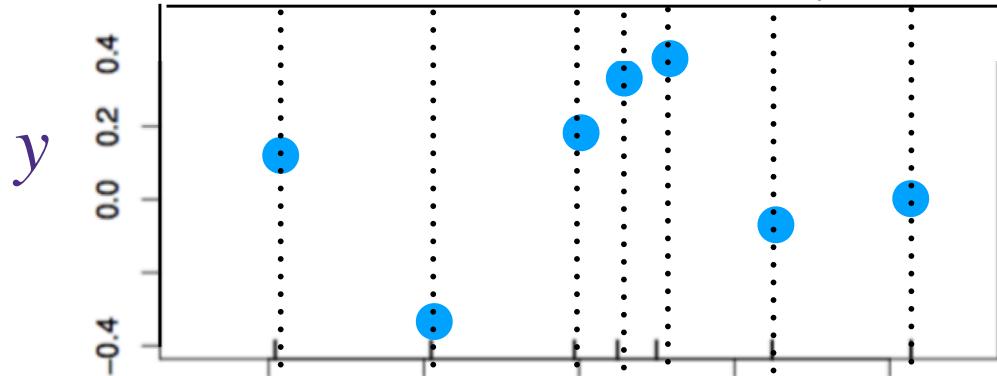
samples $\{(x_i, y_i)\}_{i=1}^n$



- predictor $f(x) = \sum_{i=1}^n \alpha_i K(x_i, x)$ is taking weighted sum of n kernel functions centered at each sample points

RBF kernel $k(x_i, x) = \exp\left\{ -\frac{\|x_i - x\|_2^2}{2\sigma^2} \right\}$

samples $\{(x_i, y_i)\}_{i=1}^n$



- predictor $f(x) = \sum_{i=1}^n \alpha_i K(x_i, x)$ is taking weighted sum of n kernel functions centered at each sample points

Why do we need regularization when using kernels?

- Typically, $p \gg d$ and $\mathbf{K} > 0$. Why?

$$K = \phi(x) \cdot \phi(x)^T$$

A hand-drawn diagram illustrating the mapping from a high-dimensional input space to a feature space. On the left, a tall vertical rectangle labeled 'n' at the top is labeled 'x' at the bottom. An arrow labeled 'phi' points to the right, leading to a shorter horizontal rectangle labeled 'p' at the bottom. This shorter rectangle is labeled 'K' at the top, representing the kernel matrix.

- So \mathbf{K} is invertible and $\hat{\alpha} = (\mathbf{K} + \lambda \mathbf{I}_{n \times n})^{-1} \mathbf{y}$ is well defined.
- What if $\lambda = 0$? What goes wrong?

$$\arg \min_{\alpha} \|\mathbf{y} - \mathbf{K}\alpha\|_2^2$$

A hand-drawn diagram illustrating the squared difference between a target vector \mathbf{y} and a predicted vector $\mathbf{K}\alpha$. It shows two rectangles side-by-side. The first rectangle on the left is labeled 'y' at the top and has a dimension of 'n'. The second rectangle on the right is labeled 'alpha' at the bottom and has a dimension of 'n'. A double-headed arrow between them is labeled with a tilde over the minus sign, indicating the squared norm of the difference between the two vectors.

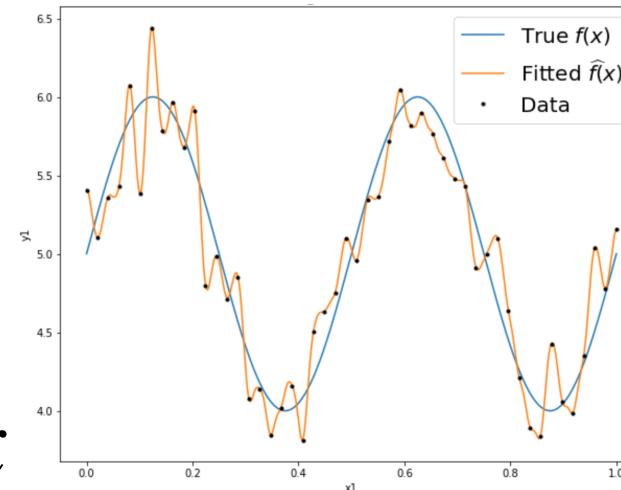
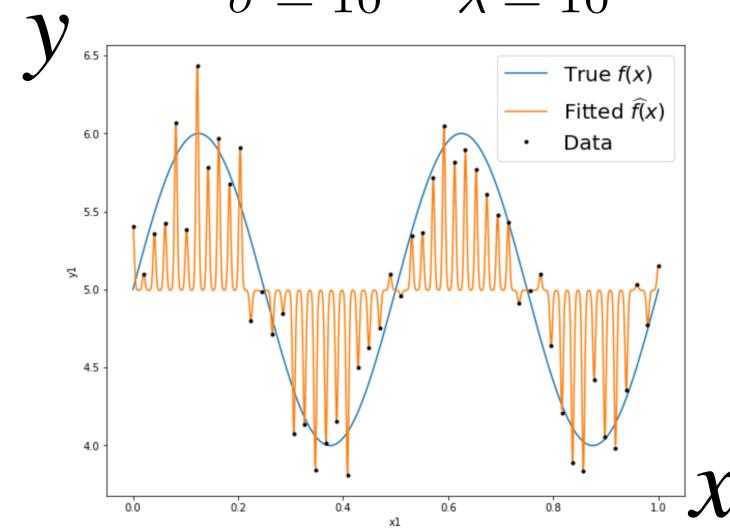
RBF kernel

$$k(x_i, x) = \exp\left\{-\frac{\|x_i - x\|_2^2}{2\sigma^2}\right\}$$

- $\mathcal{L}(\alpha) = \|\mathbf{K}\alpha - \mathbf{y}\|_2^2 + \lambda\|w\|_2^2$
- The bandwidth σ^2 of the kernel regularizes the predictor, and the regularization coefficient λ also regularizes the predictor

$$\sigma = 10^{-3} \quad \lambda = 10^{-4}$$

$$\sigma = 10^{-2} \quad \lambda = 10^{-4}$$



$$\hat{f}(x) = \sum_{i=1}^n \hat{\alpha}_i K(x_i, x)$$

RBF kernel

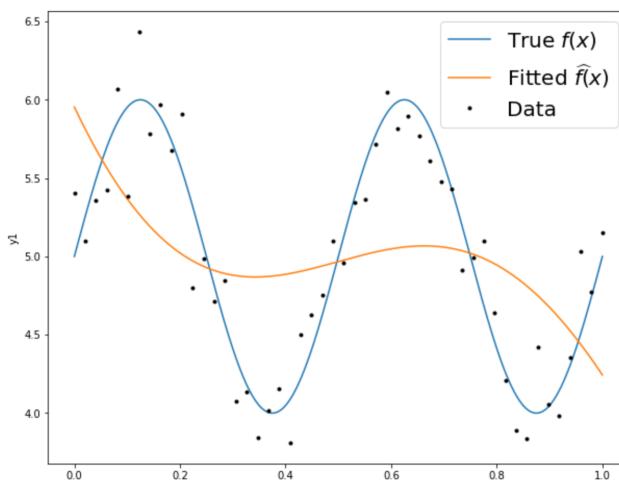
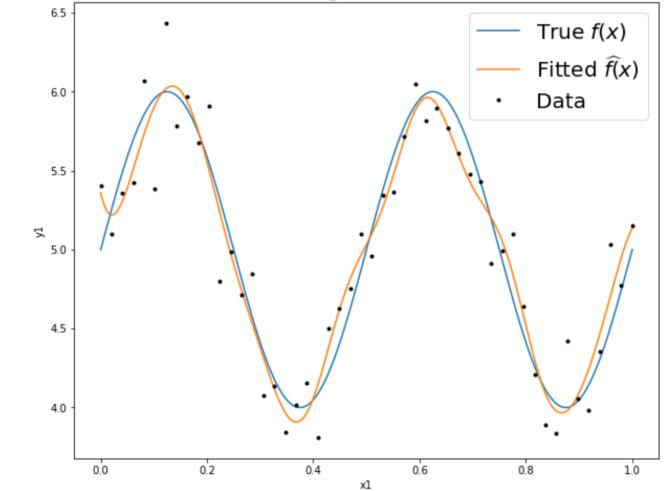
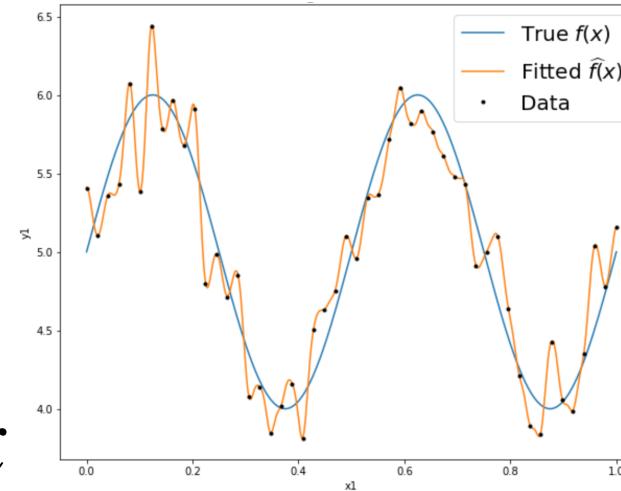
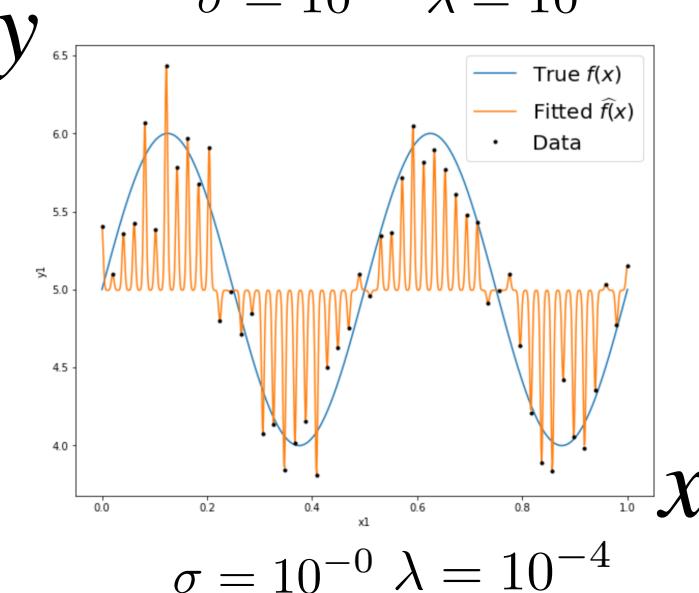
$$k(x_i, x) = \exp\left\{-\frac{\|x_i - x\|_2^2}{2\sigma^2}\right\}$$

- $\mathcal{L}(\alpha) = \|\mathbf{K}\alpha - \mathbf{y}\|_2^2 + \lambda\|w\|_2^2$
- The bandwidth σ^2 of the kernel regularizes the predictor, and the regularization coefficient λ also regularizes the predictor

$$\sigma = 10^{-3} \quad \lambda = 10^{-4}$$

$$\sigma = 10^{-2} \quad \lambda = 10^{-4}$$

$$\sigma = 10^{-1} \quad \lambda = 10^{-4}$$



$$\hat{f}(x) = \sum_{i=1}^n \hat{\alpha}_i K(x_i, x)$$

RBF kernel

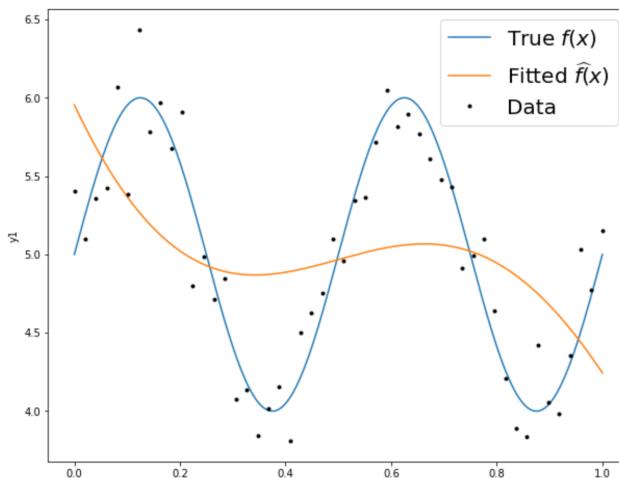
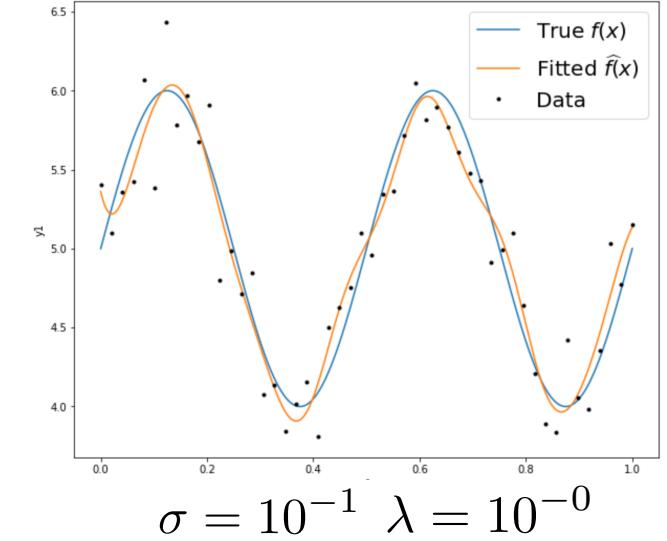
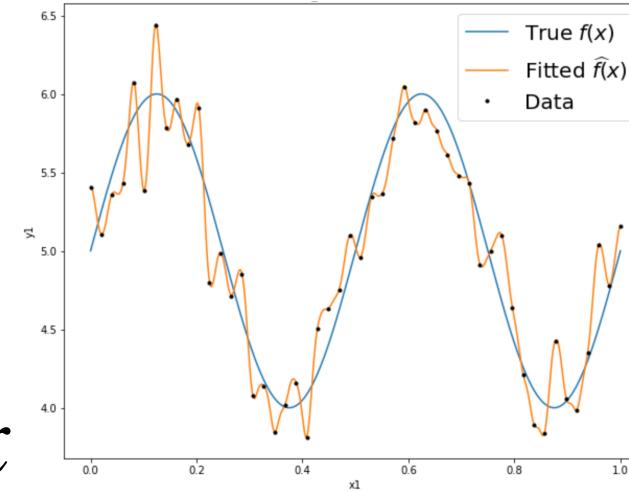
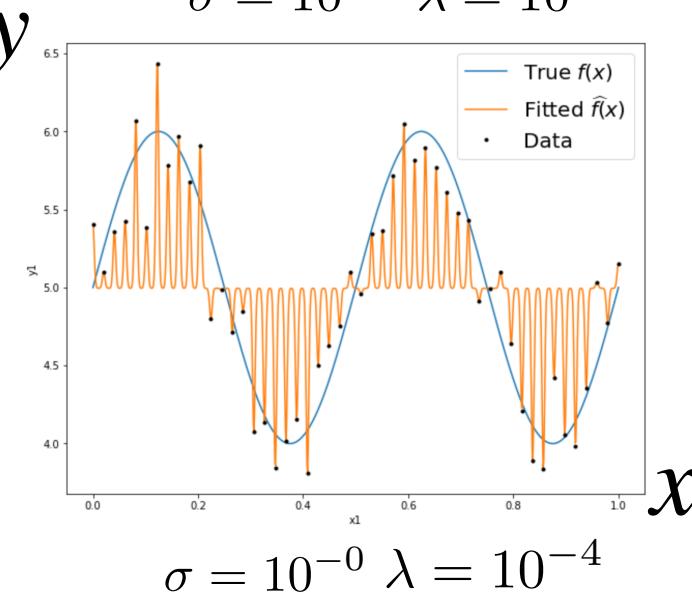
$$k(x_i, x) = \exp\left\{-\frac{\|x_i - x\|_2^2}{2\sigma^2}\right\}$$

- $\mathcal{L}(\alpha) = \|\mathbf{K}\alpha - \mathbf{y}\|_2^2 + \lambda\|w\|_2^2$
- The bandwidth σ^2 of the kernel regularizes the predictor, and the regularization coefficient λ also regularizes the predictor

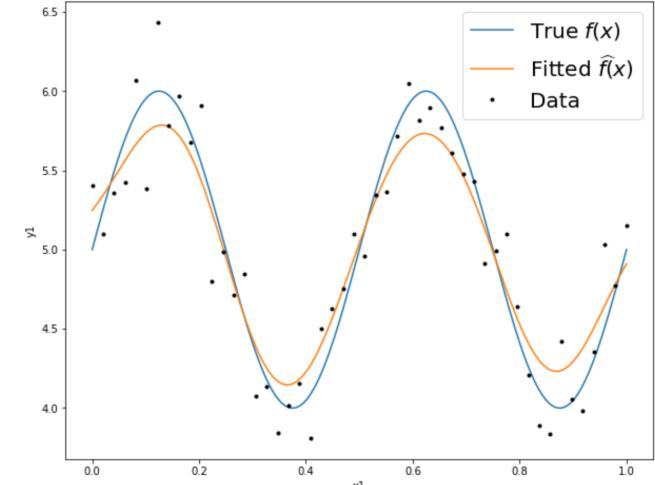
$$\sigma = 10^{-3} \quad \lambda = 10^{-4}$$

$$\sigma = 10^{-2} \quad \lambda = 10^{-4}$$

$$\sigma = 10^{-1} \quad \lambda = 10^{-4}$$



$$\hat{f}(x) = \sum_{i=1}^n \hat{\alpha}_i K(x_i, x)$$

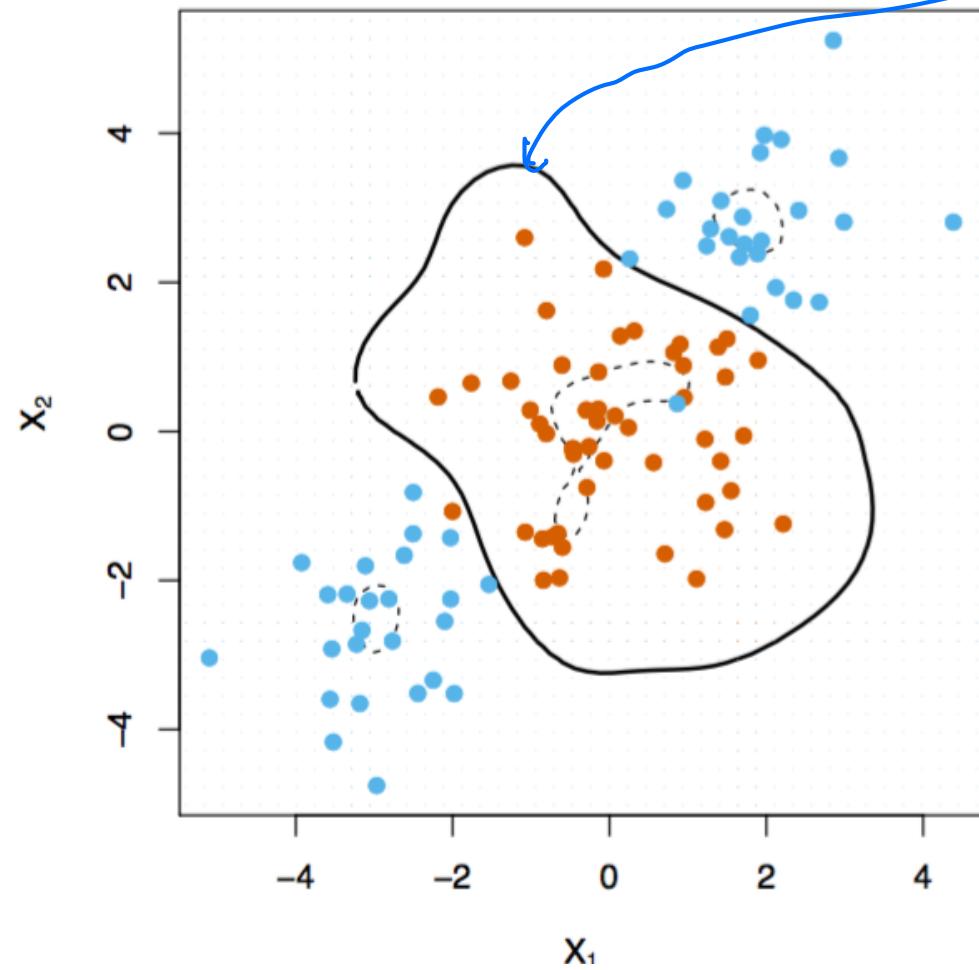


RBF kernel and random features

$$k(x_i, x) = \exp\left\{-\frac{\|x_i - x\|_2^2}{2\sigma^2}\right\}$$

Bandwidth σ is large enough

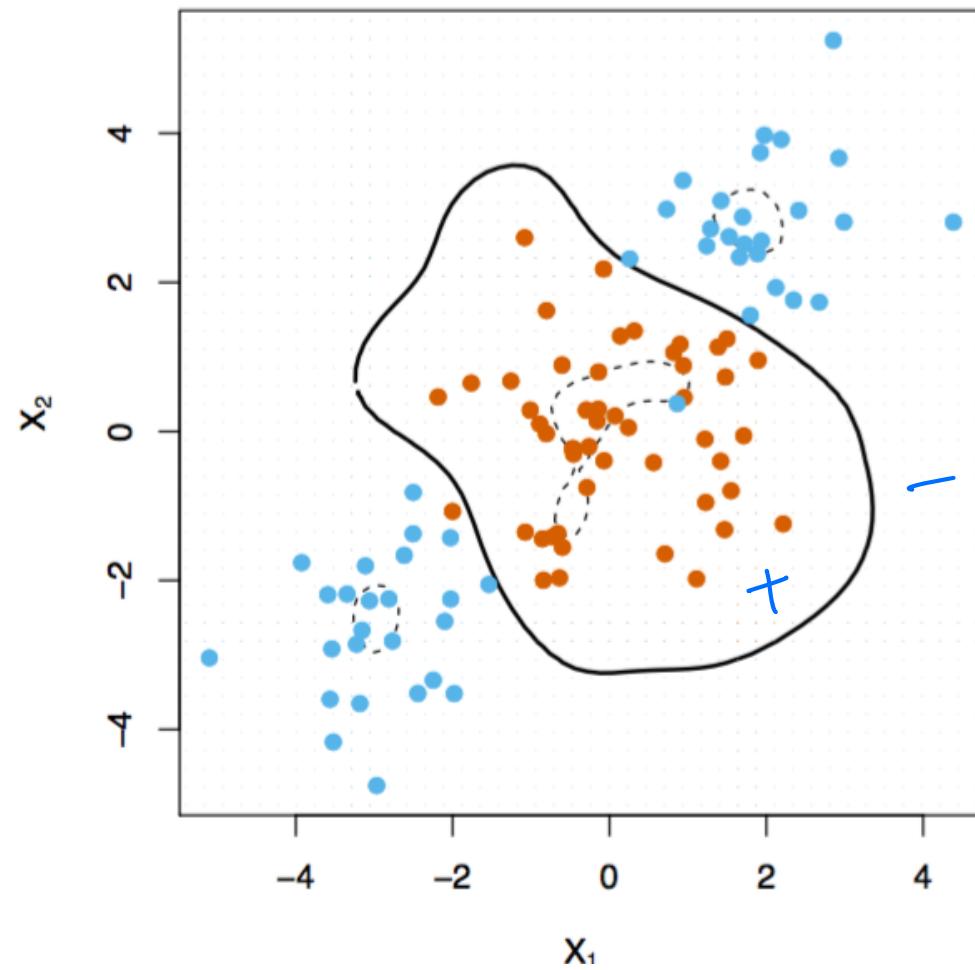
right decision boundary



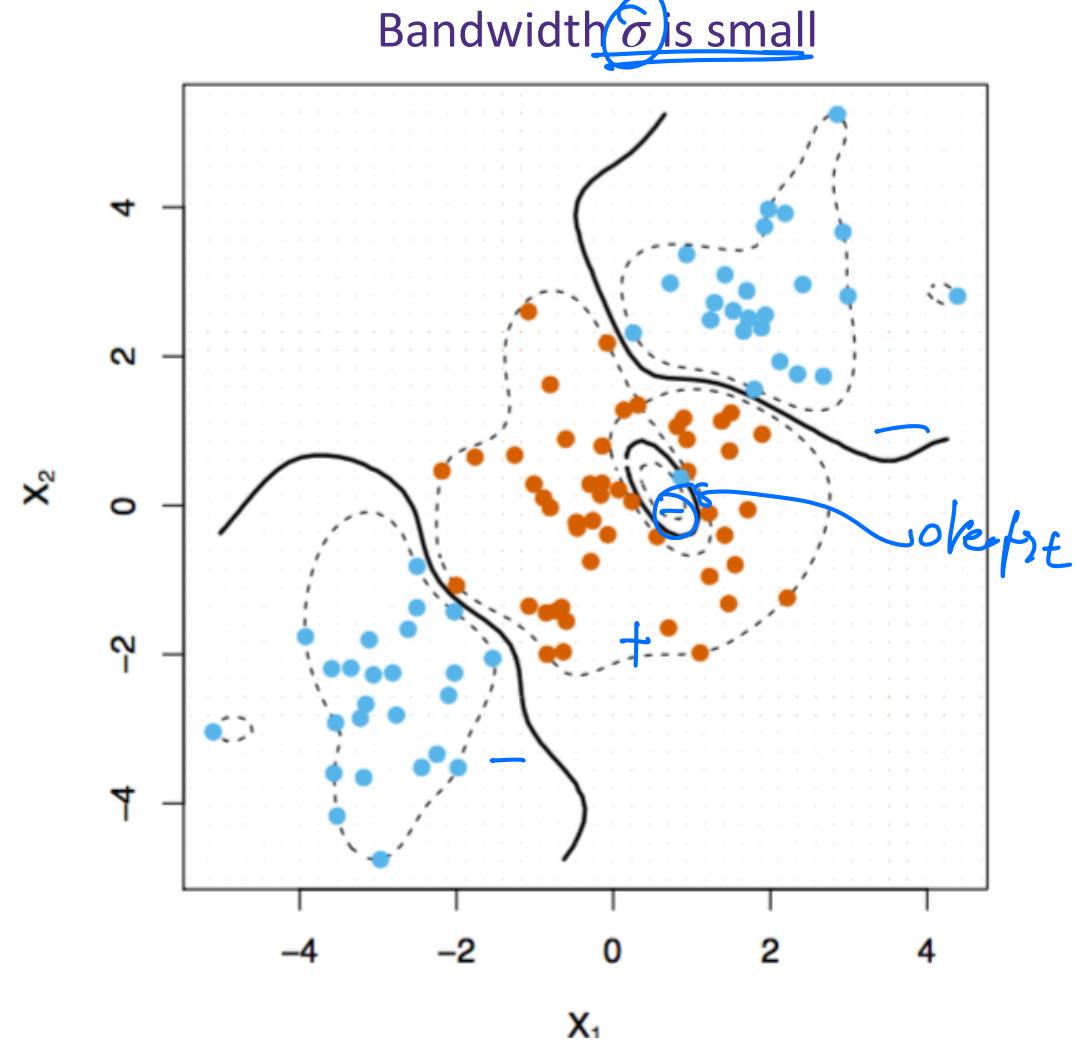
RBF kernel and random features

$$k(x_i, x) = \exp\left\{-\frac{\|x_i - x\|_2^2}{2\sigma^2}\right\}$$

Bandwidth σ is large enough



Bandwidth σ is small



Fixed Feature V.S. Learned Feature

- Kernel method works well if we choose a good kernel such that the data is linearly separable in the corresponding (possibly infinite dimensional) feature space
- In practice, it is hard to choose a good kernel for a given problem
- Can we **learn** the feature mapping $\phi : \mathbb{R}^d \rightarrow \mathbb{R}^p$ from data also?

Questions?
