# 实验报告

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## 实验步骤

任务一

安装vscode

```
nju@nju: ~/dl
                                              Q
                                   获取并检查 snap "code" (184) 的ass
                                        获取并检查 snap "code" (184)
ertion
                                             获取并检查 snap "code"
的assertion
 (184) 的assertion
                                                   获取并检查 snap
"code" (184) 的asserti<u>o</u>n
                                                        挂载 snap
                                                             挂载
code" (184)
 snap "code" (184)
 挂载 snap "code" (184)
      挂载 snap "code" (184)
            设置 snap "code" (184) 的安全配置
                 设置 snap "code" (184) 的安全配置
                      设置 snap "code" (184) 的安全配置
                            设置 snap "code" (184) 的安全配置
                                 设置 snap "code" (184) 的安全配置
                                      设置 snap "code" (184) 的安全
配置
                                            设置 snap "code" (184)
的安全配置
                                                  设置 snap "code"
(184) 的安全配置
                                                       使 snap "co
de" (184) 可用于系统
                                                            如果
存在,则运行 "code" snap 的配置钩子
 code e54c774e from Visual Studio Code (vscode√) installed
nju@nju:~/dl$
```

安装docker并测试docker成功安装

```
正在设置 libnvidia-container-tools (1.13.5-1) ...
正在设置 nvidia-container-toolkit (1.13.5-1) ...
正在处理用于 libc-bin (2.35-0ubuntu3.9) 的触发器
        "registry-mirrors": [
"https://docker.ins.run",
"https://docker.uanyuan.ne",
"https://docker.nju.edu.cn",
"https://do.nark.eu.org",
"https://do.nark.eu.org",
"https://docker.n.daocloud.to",
"https://docker.n.daoc.com"
                  "https://dockerproxy.com",
"https://docker.mirrors.ustc.edu.cn"
        or:avrides": {
    "nvidia": {
    "path": "nvidia-container-runtine",
    "runtineArgs": []
    jugnju:/etc/apt/sources.list./5 docker run hello-world ocker: permission dented while trying to connect to the Docker daemon socket at unix:///var/run/docker.sock: Head "http://%2Fvar%2Frun%2Fdocker.sock/_ping": dial unix /var/run/docker.sock: connect: permi
 Judghy/stc/pb/fsources.ltstd9 newgrp docker
judghy/stc/pb/fsources.ltstd9 newgrp docker
judghy/stc/pb/fsources.ltstd9 docker nown hello-world
lmable to find image 'hello-world:latest' locally
latest: Pulling from library/hello-world
a6599344b185: Pull complete
Digest: sha256:e0b5993516335e0be84e21002587e7d447e08f87a0e90798363fa44a0464a1e8
Status: Downloaded newer Image for hello-world:latest
   his message shows that your installation appears to be working correctly.
```

### 创建并运行基础容器

```
Dimmin:/est/ast/sources.list./$ docker run -tt --gpus all --name my-pytorch-env -v -/:/workspace ubuntu:22.04 /bln/bash.

Drable to find image 'ubuntu:22.04' locally

82.04: Pulling from library/ubuntu

92.04: Pulling from library/ubuntu

92.05: Pulling from library/ubuntu

10.053162278:a: Pull complete

10.053162278:a: Pull complete

10.053162378:a: Domnloaded newer image for ubuntu:22.04

10.053162378:a: Domnloaded newer image for ubuntu:22.04

10.053162378:a: Pulling from library/ubuntu:22.04

10.05316316: Pulling from library/ubuntu:22.04

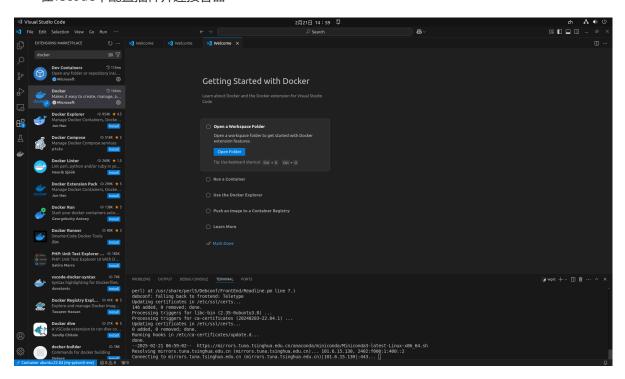
10.05316316: Pulling from library/ubuntu:22.04

10.05316316: Pulling from library/ubuntu:22.04

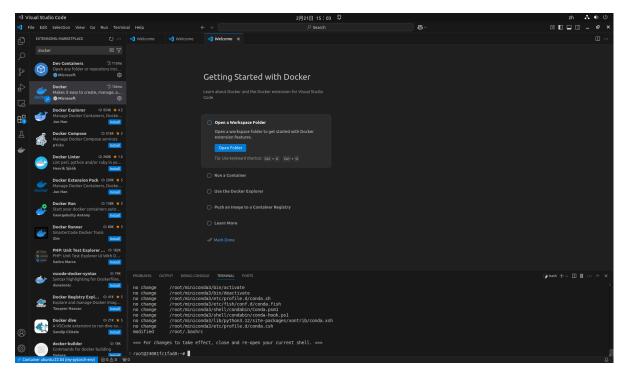
10.05316316: Pulling from library/ubuntu:22.04

10.05316: Pulling from library/ubuntu:22.04
```

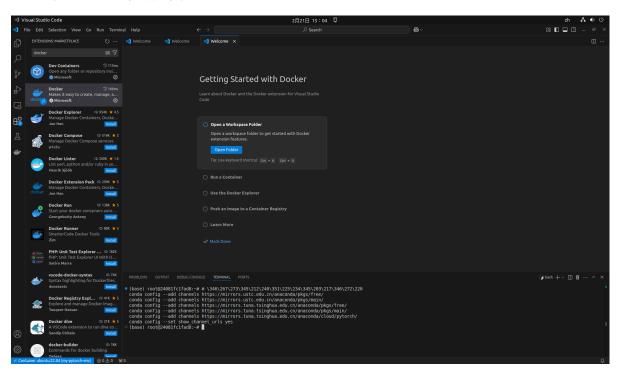
### 在vscode中配置插件并连接容器



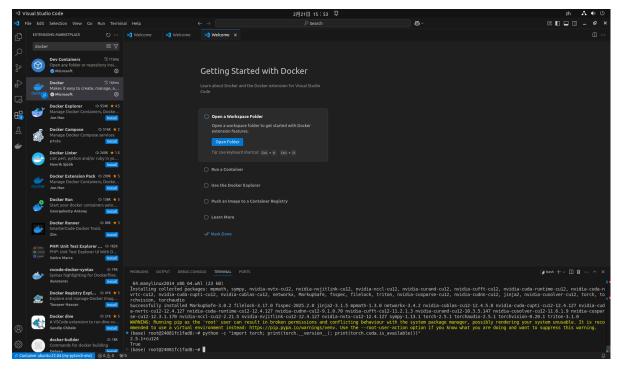
在vscode中加载docker环境



安装miniconda,添加镜像源



安装pytorch环境



#### 任务二

### 完成第五节,输出如图

```
"""构造一个PyTorch数据迭代器。"""
                                                                                                                                                          ↑ ↓ ♦ 🗗 🗎 🗎
0
                 dataset = data. TensorDataset (*data_arrays)
                 \tt return - data. \, DataLoader \, (dataset, - batch\_size, - shuffle=is\_train)
      batch_size = 10
data_iter = load_array((features, labels), batch_size)
      net = nn. Sequential (nn. Linear (2, 1)) #线性层
      \label{eq:net_0} \begin{split} & \texttt{net[0]}.\, \texttt{weight}.\, \texttt{data}.\, \texttt{normal}\_(0, \quad 0.\,\, 01) \\ & \texttt{net[0]}.\, \texttt{bias}.\, \texttt{data}.\, \texttt{fill}\_(0) \end{split}
      loss = nn. MSELoss()
trainer = torch.optim. SGD(net.parameters(), 1r=0.03)
     1 = loss(net(X), y)
                            #T0D0:清空梯度
                           trainer.zero_grad()
#TODO:反向传播
                            1. backward()
                           #TODO:优化器更新参数
                           trainer. step()
                 1 = loss(net(features), labels)
print(f'epoch {epoch + 1}, loss {1:f}')
epoch 1, loss 0.000166
epoch 2, loss 0.000098
epoch 3, loss 0.000098
```