Support Vector Machines

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CONTENTS

Abstract—This manual provides an introduction to SVM.

1 REFLECTION

1.1 Find the distance of $\mathbf{x}_1 = \begin{pmatrix} 2 \\ 1 \end{pmatrix}$ from the line

$$\begin{pmatrix} 3 & 4 \end{pmatrix} \mathbf{x} + 5 = 0 \qquad (1.1)$$

1.2 Show that the distance of the point $\mathbf{x}_1$ from the line

$$\mathbf{n}^T \mathbf{x} + c = 0, \quad \|\mathbf{n}\| = 1 \qquad (1.2)$$

is

$$M = \left| \mathbf{n}^T \mathbf{x}_1 + c \right| \qquad (1.3)$$

1.3 Find the reflection $\mathbf{x}_2$ of $\mathbf{x}_1$.

1.4 Define

$$f(\mathbf{x}) = \mathbf{n}^T \mathbf{x} + c \qquad (1.4)$$

1.5 Compute $f(\mathbf{x}_1)$ and $f(\mathbf{x}_2)$. Comment.

2 OPTIMIZATION PROBLEM

2.1 Suppose $(\mathbf{x}_1, y_1)$ and $(\mathbf{x}_2, y_2)$ are i/o data for a system where $y_1, y_2 \in \{1, -1\}$. If you want to find $\mathbf{n}, c$ from the given dataset, how will

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formulate the equivalent optimization problem?

Solution: Consider the optimization problem

$$\max_{\mathbf{n},c} M \qquad (2.1)$$

$$\text{s.t} \quad y_1 \left(\mathbf{x}_1^T \mathbf{n} + c \right) \geq M \qquad (2.2)$$

$$y_2 \left(\mathbf{x}_2^T \mathbf{n} + c \right) \geq M \qquad (2.3)$$

$$\|\mathbf{n}\| = 1 \qquad (2.4)$$

2.2 The *signum* function is defined as

$$\text{sgn}(z) = \begin{cases} 1 & z > 0 \\ 0 & z = 0 \\ -1 & z < 0 \end{cases} \qquad (2.5)$$

Show that

$$\text{sgn}(\mathbf{x}^T \mathbf{n} + c) = \text{sgn}(\mathbf{x}^T \mathbf{w} + d) \qquad (2.6)$$

where

$$\mathbf{w} = \frac{\mathbf{n}}{M}, d = \frac{c}{M}, M > 0 \qquad (2.7)$$

2.3 Show that (2.1)-(2.4) can be reformulated as

$$\min_{\mathbf{w},d} \frac{1}{2} \|\mathbf{w}\|^2 \qquad (2.8)$$

$$\text{s.t} \quad y_i \left(\mathbf{x}_i^T \mathbf{w} + d \right) \geq 1 \qquad (2.9)$$

Solution: From (2.7),

$$\mathbf{w} = \frac{\mathbf{n}}{M} \implies \|\mathbf{w}\| = \frac{\|\mathbf{n}\|}{M} \qquad (2.10)$$

$$\implies M = \frac{1}{\|\mathbf{w}\|} \because \|n\| = 1 \qquad (2.11)$$

Thus,

$$\max_{\mathbf{n},c} M = \max_{\mathbf{w},d} \frac{1}{\|\mathbf{w}\|} = \min_{\mathbf{w},d} \|\mathbf{w}\|. \qquad (2.12)$$

Also, (2.2)-(2.3) become

$$y_i \left(\mathbf{x}_i^T \mathbf{w} + d \right) \geq 1 \qquad (2.13)$$

3 SOLVER

3.1 Solve (2.8) using *cvxpy/cvxopt* for $\mathbf{x}_1 = \begin{pmatrix} 2 \\ 1 \end{pmatrix}, y_1 = 1$ and $\mathbf{x}_2 = \begin{pmatrix} 0.8 \\ -0.6 \end{pmatrix}, y_2 = -1$.

Solution: From the given information, the constraints in (2.8) become

$$\begin{pmatrix} 2 & 1 \end{pmatrix} \mathbf{w} + d \geq 1 \qquad (3.1)$$

$$\begin{pmatrix} 0.8 & -0.6 \end{pmatrix} \mathbf{w} + d \leq -1 \qquad (3.2)$$

The following code results in

$$\mathbf{w}_{opt} = \begin{pmatrix} 0.6 & 0.8 \end{pmatrix}, d_{opt} = 1, \left\| \mathbf{w}_{opt} \right\|^2 = 1 \quad (3.3)$$

```
from cvxpy import *
import numpy as np

# x is array of datapoints stacked column
    wise [x1, x2, ... , xn]
x = np.array([
        [ 2.0, 0.8 ] ,
        [ 1.0, −0.6 ]
        ])

# y is matrix with labels stacked diagonally
y = np.diag([1,−1])

n=2 #no of datapoints
p=2 #no of parameters of each datapoint

d= Variable()
d_v = np.ones((p,1))*d
#broadcasted d into a vector d_v

w = Variable((p,1),nonneg=False)

#objective function
obj = Minimize(0.5*square(norm(w)))

#constraints
constraints = [((x@y).T)@w + y@d_v>= np
    .ones((n,1))]

Problem(obj, constraints).solve()
print("Minimum value of Cost function= ",
    obj.value)
print("Minima is at w = \n",w.value)
print("Minima is at d= ",d.value)
```

3.2 Provide a graphical representation for (2.8)

Solution: The following code plots Fig. 3.2.

The constraint lines in (3.1)-(3.2) are plotted for $d = 0, 0.5$ and 1. The circles $\|\mathbf{w}\|^2 = r^2$ are plotted for $r = 1, 2$ and 3. The smalles circle that satisfies the constraints is obtained when $d = 1$

wget https://raw.githubusercontent.com/
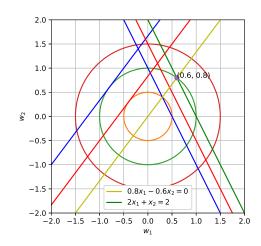   gadepall/EE1390/master/manuals/svm/
    codes/svm_graph.py

Fig. 3.2

4 KKT SOLUTION

4.1 Show that the Lagrangian for (2.8) can be expressed as

$$L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) = \frac{1}{2} \|\mathbf{w}\|^2$$
$$- \boldsymbol{\alpha}^T \left(\begin{pmatrix} y_1 \mathbf{x}_1 & y_2 \mathbf{x}_2 \end{pmatrix}^T \mathbf{w} + d \begin{pmatrix} y_1 \\ y_2 \end{pmatrix} - \begin{pmatrix} 1 \\ 1 \end{pmatrix}\right) \quad (4.1)$$

where

$$\boldsymbol{\alpha} = \begin{pmatrix} \alpha_1 \\ \alpha_2 \end{pmatrix} \qquad (4.2)$$

are the Lagrange multipliers.

Solution: The Lagrangian is given by,

$$L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) = \frac{1}{2} \|\mathbf{w}\|^2$$
$$- \sum_{i=1}^{2} \alpha_i \left\{ y_i \left(\mathbf{x}_i^T \mathbf{w} + d \right) - 1 \right\} \quad (4.3)$$

which can be simplified to obtain (4.1)

4.2 Show that the stationarity condtion with respect to $\mathbf{w}$ yields

$$\left(\mathbf{I} \quad -\begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix} \quad \mathbf{0}\right)\begin{pmatrix} \mathbf{w} \\ \boldsymbol{\alpha} \\ d \end{pmatrix} = 0 \qquad (4.4)$$

Solution: From the stationarity condition

$$\nabla_{\mathbf{w}}L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) = 0 \qquad (4.5)$$

$$\text{or,} \quad \mathbf{w} - \begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix}\boldsymbol{\alpha} = 0 \qquad (4.6)$$

resulting in (4.4).

4.3 Show that the stationarity condition with respect to $\boldsymbol{\alpha}$ yields

$$\left(\begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix}^T \quad \mathbf{0} \quad \begin{pmatrix} y_1 \\ y_2 \end{pmatrix}\right)\begin{pmatrix} \mathbf{w} \\ \boldsymbol{\alpha} \\ d \end{pmatrix} = \begin{pmatrix} 1 \\ 1 \end{pmatrix} \qquad (4.7)$$

Solution:

$$\nabla_{\boldsymbol{\alpha}}L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) = 0 \qquad (4.8)$$

$$\implies \begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix}^T\mathbf{w} + d\begin{pmatrix} y_1 \\ y_2 \end{pmatrix} - \begin{pmatrix} 1 \\ 1 \end{pmatrix} = 0 \qquad (4.9)$$

after simplification resulting in (4.7)

4.4 Find the stationarity condition with respect to d.

Solution:

$$\nabla_d L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) = 0 \qquad (4.10)$$

$$\implies \begin{pmatrix} y_1 & y_2 \end{pmatrix}\boldsymbol{\alpha} = 0 \qquad (4.11)$$

$$\text{or,} \quad \begin{pmatrix} \mathbf{0} & \begin{pmatrix} y_1 & y_2 \end{pmatrix} & 0 \end{pmatrix}\begin{pmatrix} \mathbf{w} \\ \boldsymbol{\alpha} \\ d \end{pmatrix} = 0 \qquad (4.12)$$

4.5 Obtain a matrix equation for $\mathbf{w}$ and d.
Solution: (4.4) (4.7) and (4.12) can be stacked into a single matrix equation as

$$\begin{pmatrix} \mathbf{I} & -\begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix} & \mathbf{0} \\ \begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix}^T & \mathbf{0} & \begin{pmatrix} y_1 \\ y_2 \end{pmatrix} \\ \mathbf{0} & \begin{pmatrix} y_1 & y_2 \end{pmatrix} & 0 \end{pmatrix}\begin{pmatrix} \mathbf{w} \\ \boldsymbol{\alpha} \\ d \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \\ 1 \\ 1 \\ 0 \end{pmatrix}$$
$$(4.13)$$

4.6 Find the optimal values of $\mathbf{w}$ and d by solving (4.13) using python.
Solution:

wget https://github.com/gadepall/EE1390/raw/
master/manuals/svm/codes/svm_matrix.py

5 Duality

5.1 Substitute (4.4) and (4.12) in the primal function to obtain the Lagrangian (Wolfe) dual objective function L_D.
Solution: From (4.4)

$$\mathbf{w} = \begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix}\boldsymbol{\alpha} \qquad (5.1)$$

$$\implies \mathbf{w}^T\mathbf{w} = \boldsymbol{\alpha}^T\begin{pmatrix} y_1\mathbf{x}_1^T \\ y_2\mathbf{x}_2^T \end{pmatrix}\begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix}\boldsymbol{\alpha} \qquad (5.2)$$

$$\text{and } \boldsymbol{\alpha}^T\begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix}^T\mathbf{w} = \mathbf{w}^T\mathbf{w} \qquad (5.3)$$

From (4.12),

$$\begin{pmatrix} y_1 & y_2 \end{pmatrix}\boldsymbol{\alpha} = 0 \qquad (5.4)$$

$$\implies \boldsymbol{\alpha}^T d\begin{pmatrix} y_1 \\ y_2 \end{pmatrix} = 0 \qquad (5.5)$$

Substituting from the above in (4.1),

$$L_D\left(\boldsymbol{\alpha}\right) = -\frac{1}{2}\boldsymbol{\alpha}^T\begin{pmatrix} y_1\mathbf{x}_1^T \\ y_2\mathbf{x}_2^T \end{pmatrix}\begin{pmatrix} y_1\mathbf{x}_1 & y_2\mathbf{x}_2 \end{pmatrix}\boldsymbol{\alpha}$$
$$+ \boldsymbol{\alpha}^T\begin{pmatrix} 1 \\ 1 \end{pmatrix} \qquad (5.6)$$

5.2 From (4.1), show that

$$L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) \le \frac{1}{2}\|\mathbf{w}\|^2 \qquad (5.7)$$

5.3 Let f^* be the solution of (2.8). Show that

$$\min_{\mathbf{w},d} L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) \le f^* \qquad (5.8)$$

5.4 Show that

$$L_D\left(\boldsymbol{\alpha}\right) = \min_{\mathbf{w},d} L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) \qquad (5.9)$$

5.5 Show that

$$f^* = \max_{\boldsymbol{\alpha}} L_D\left(\boldsymbol{\alpha}\right) \qquad (5.10)$$

$$s.t. \quad \boldsymbol{\alpha} \ge 0 \qquad (5.11)$$

$$\nabla_d L_p\left(\mathbf{w}, \boldsymbol{\alpha}, d\right) = 0 \qquad (5.12)$$

Solution:

wget https://github.com/gadepall/EE1390/raw/
master/manuals/svm/codes/wolfe_dual.py

5.6 Verify the above result by theoretically solving (5.10).