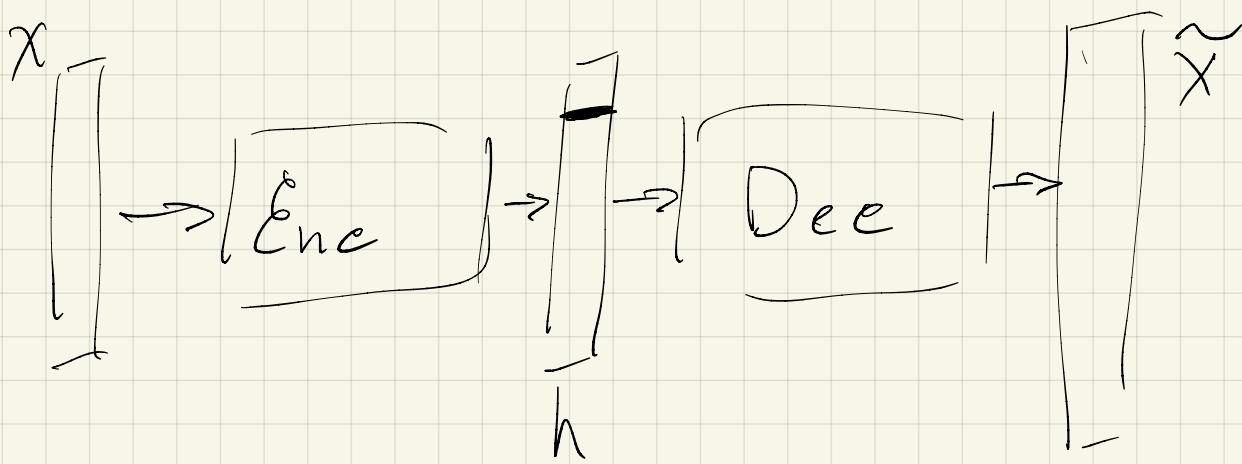


$$KL(p\|q) = - \sum p \log \frac{q}{p}$$

$$KL(B(p)\|h) = - \sum_{j=1}^k \left[ p \log \frac{p}{h_j} + (1-p) \log \frac{(1-p)}{(1-h_j)} \right]$$

$$BCE(p, q) = H(p) + KL(p\|q)$$

$$H(p) = - \sum_{x \sim p(x)} p(x) \log p(x)$$



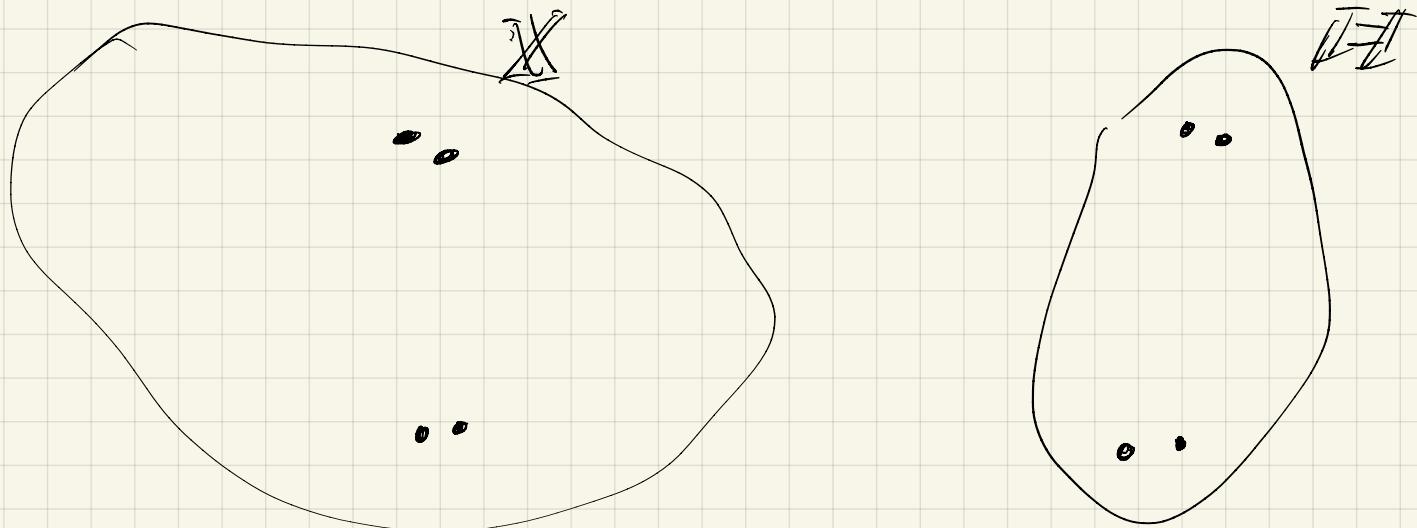
$$\mathcal{L} = \text{MSE}(\mathbf{D}(E(x)), \tilde{x})$$

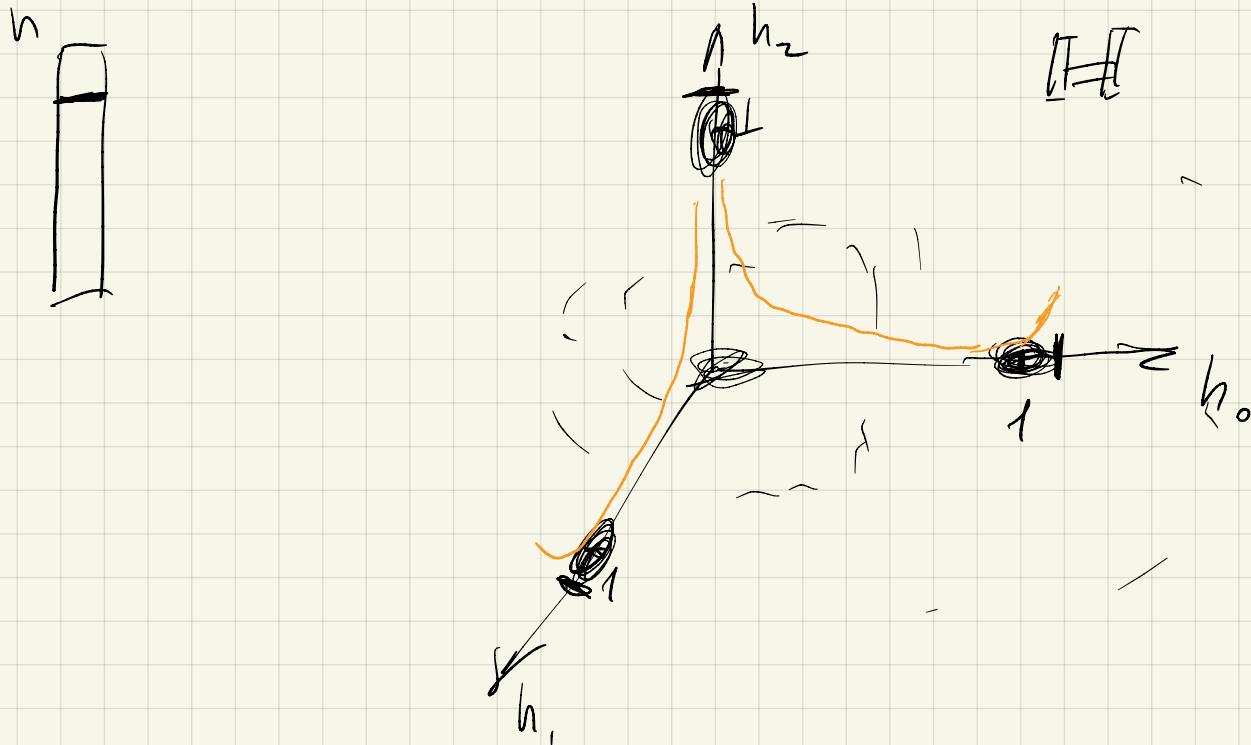
Denoising autoencoders

$$x = x + \epsilon \quad \epsilon \sim \mathcal{N}(0, G)$$

$y = x$

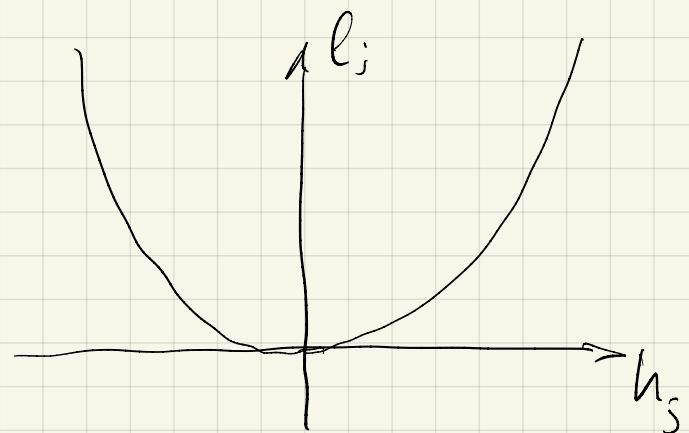
$$h_i \in \mathbb{R}^n \quad \mathbb{R}^n = \mathbb{R}^n$$





$$\mathcal{L} = \text{MSE}(\hat{D}(E(x)), x) + \ell$$

$$\frac{1}{N} \sum_{i=1}^N$$

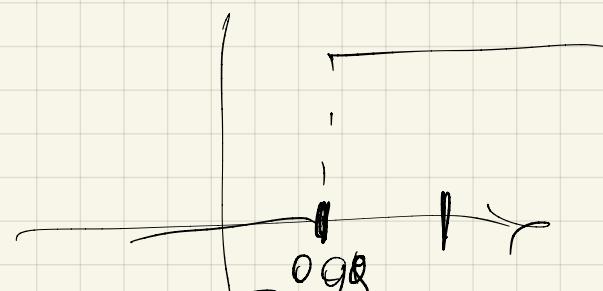


$$\textcircled{1} \quad \ell = \frac{1}{N} \sum_{j=1}^N h_j^2$$

$$\textcircled{2} \quad h_j \sim \text{Ber}(p)$$

$$p = 0,05$$

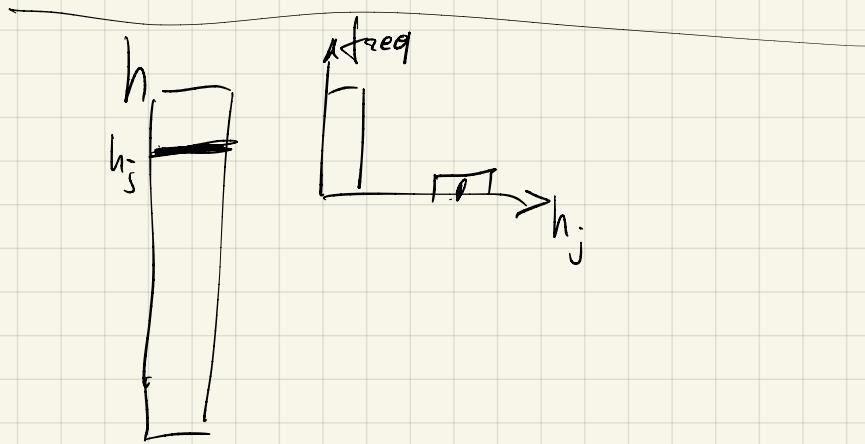
Дубліческісіз Қызыларка - Революция



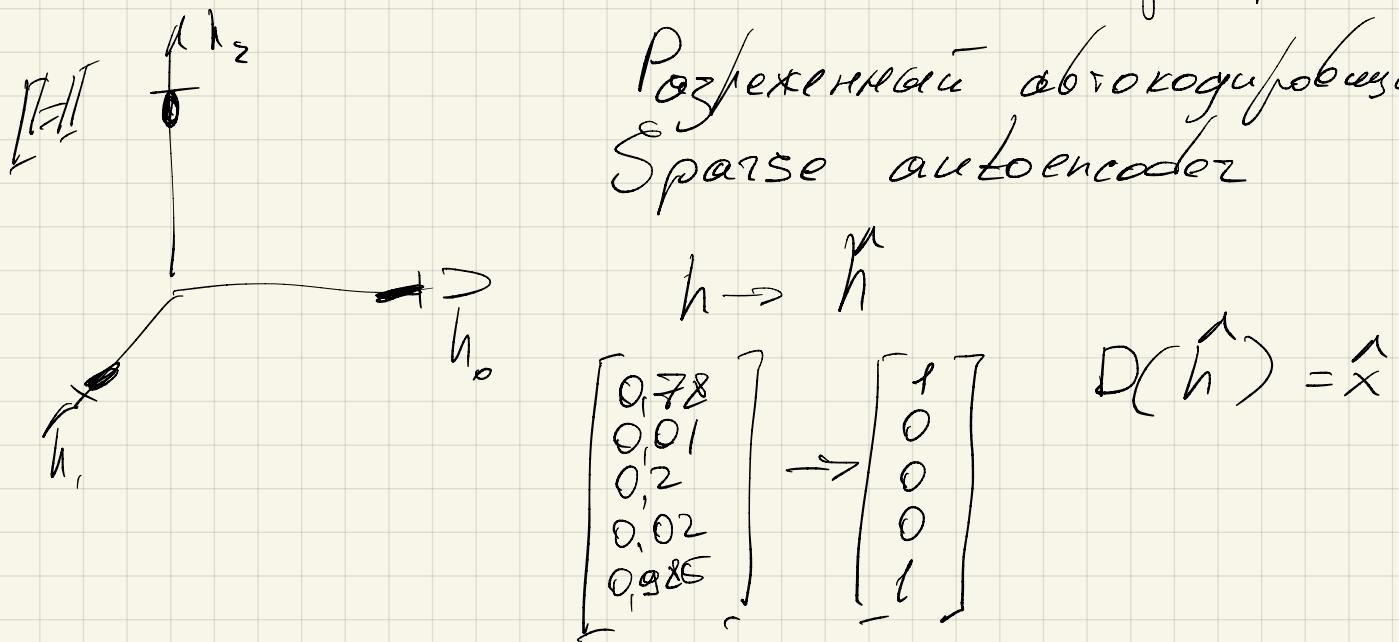
$$\text{KL}(p(x), q(x)) = \int_{x \in X} p(x) \log \frac{p(x)}{q(x)} dx$$

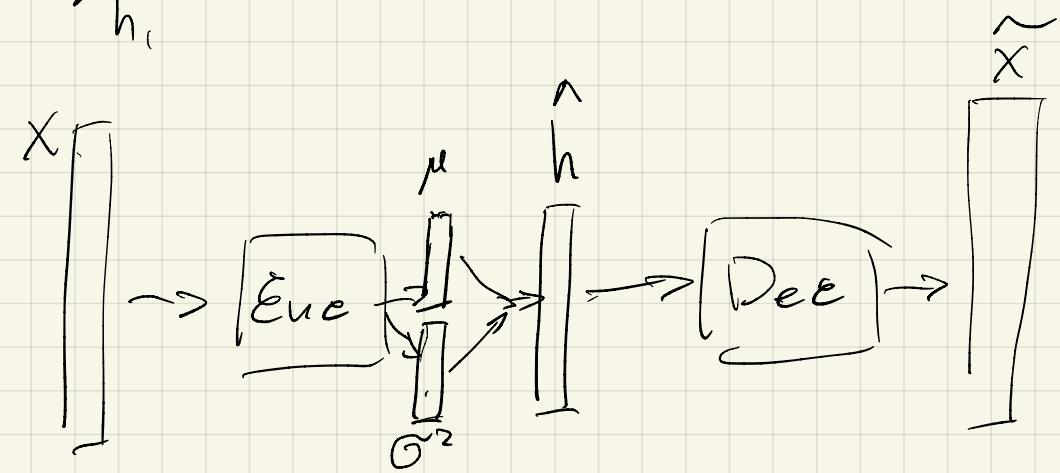
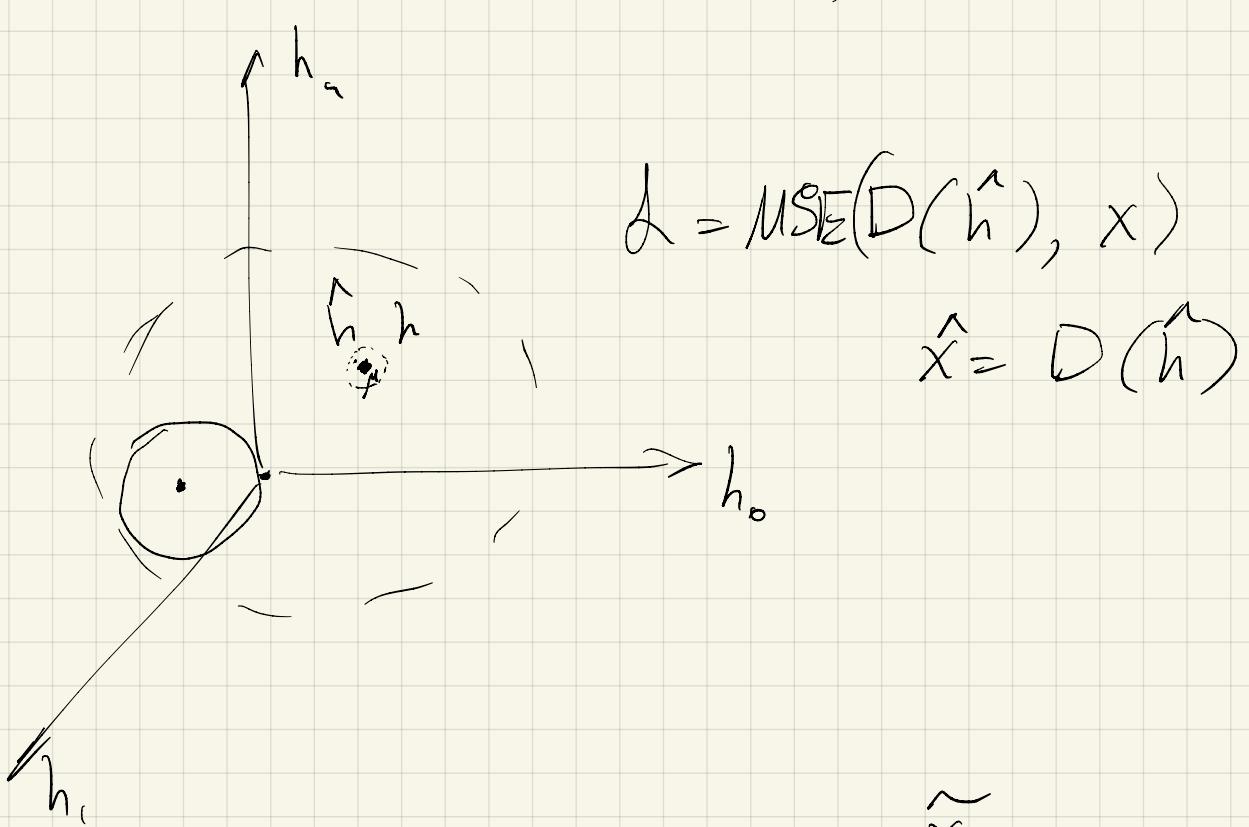
$$KL(Bez(p), p(h)) = - \sum_{j=1}^h \left[ p \log \frac{p}{h_j} + (1-p) \log \frac{(1-p)}{1-h_j} \right]$$

$$BCE(p, h) = \left( \sum_{i=1}^N h_i \log p + (1-h_i) \log (1-p) \right)$$



$$\mathcal{L} = MSE(D(\epsilon(x)), x) + \lambda KL(Bez(p), p(h))$$





$$L(\hat{x}, \tilde{x}) = \text{MSE}(x, \hat{x}) + C$$

$$\hat{h} \sim \mathcal{N}(\mu_h, \Sigma_h)$$

$$\mu_h, \ln(\sigma^2) = \mathcal{E}(x)$$

$$G^2 = e^{\ln(G^2)}$$

$$KL(\hat{h}, \mathcal{N}(\mu, G^2)) = \sum_i \left[ \frac{1}{2} \left[ \sum_i \mu_i^2 + \sum_i G_i^2 \right] - \sum_i (\log G_i + 1) \right]$$

$$\begin{array}{c} \mu \\ \text{---} \\ \sigma^2 \\ \text{---} \end{array} \xrightarrow{\quad} \boxed{\quad} \quad h \sim \mathcal{N}(\mu, \sigma^2)$$

$$s \sim \mathcal{N}(0, 1)$$

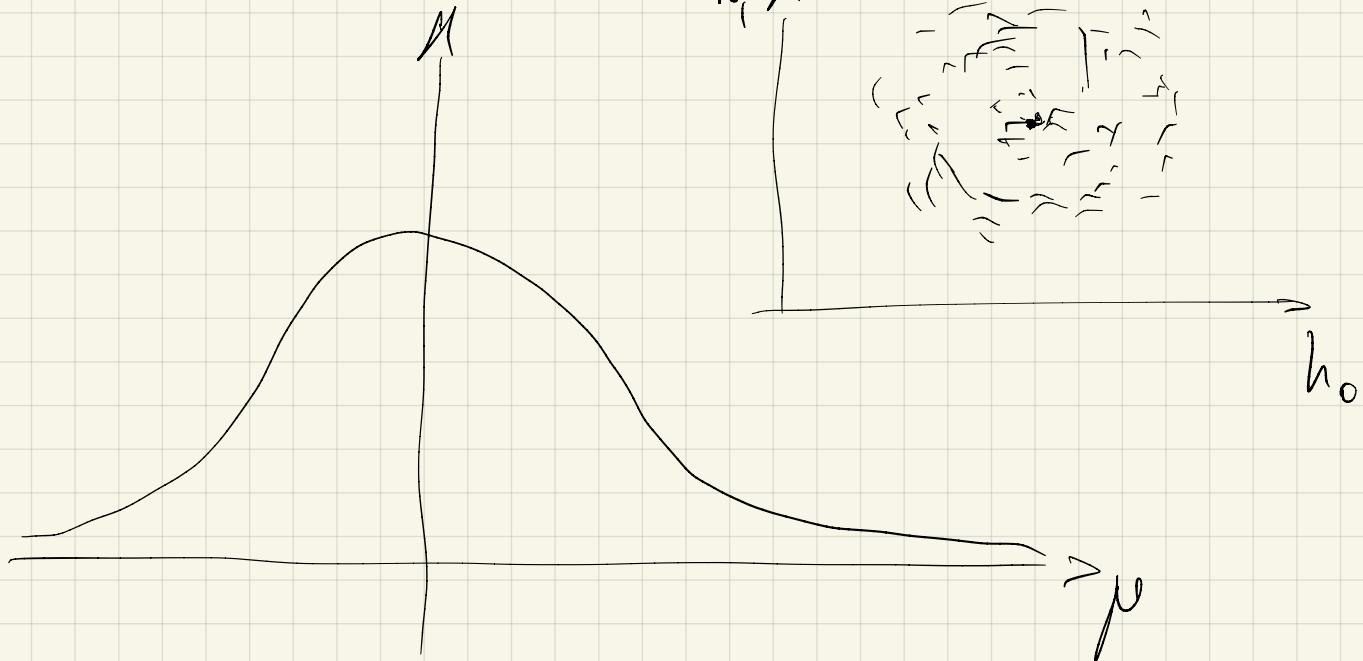
$$h = s \cdot G + \mu$$

$$x \sim \mathcal{N}(\mu - \mu_0) \Leftrightarrow x \sim \mathcal{N}(\mu) + \mu_0$$

$$x \sim \mathcal{N}((k\sigma)^2) \Leftrightarrow x \sim k\mathcal{N}(\sigma^2)$$

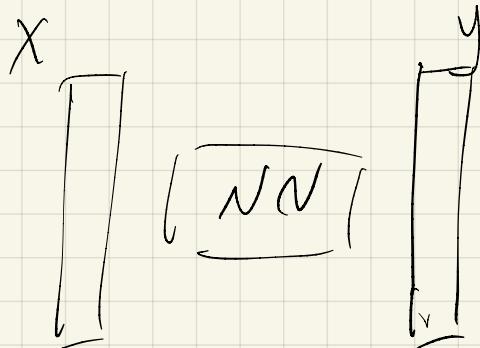
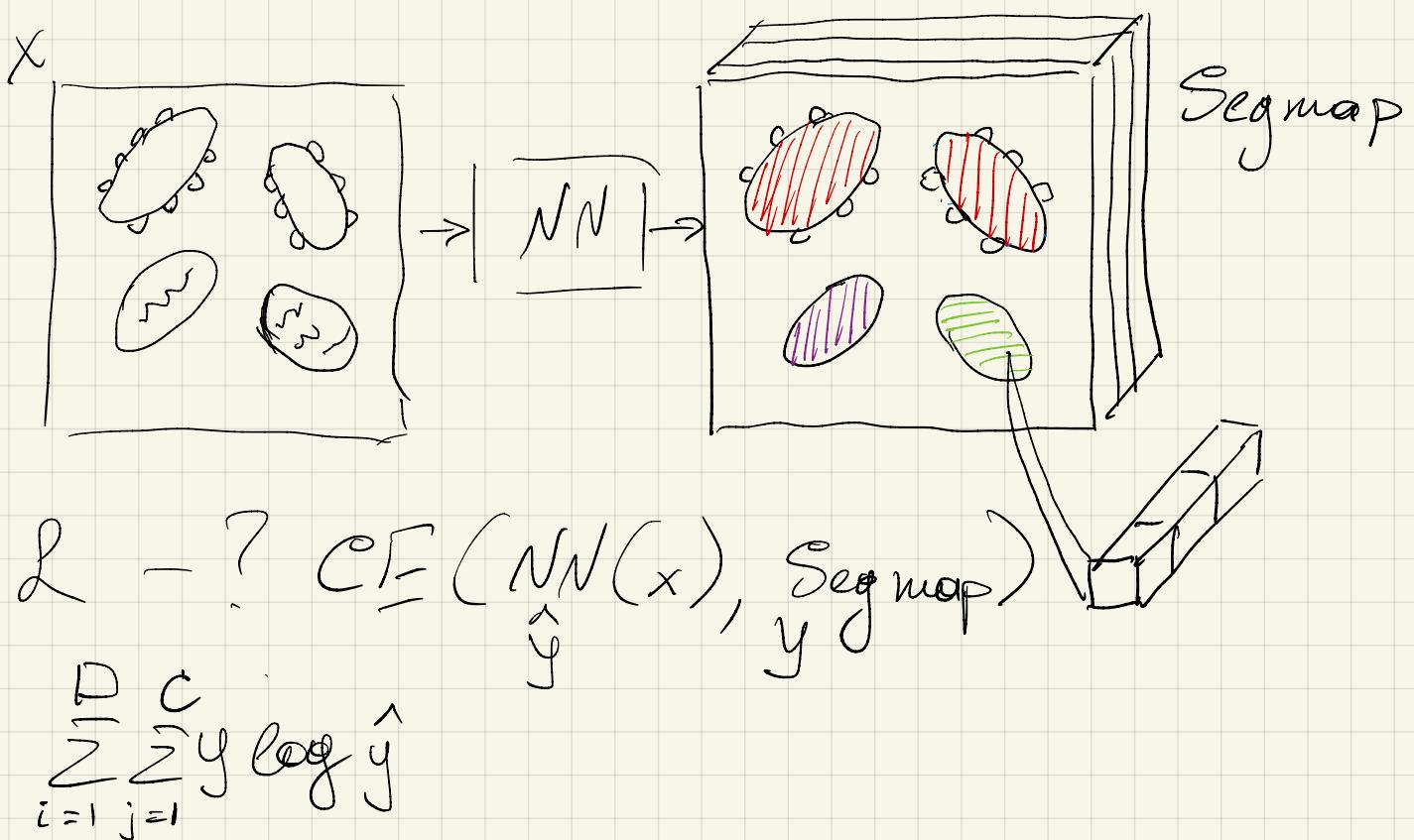
$$\mu G^2 = \mathbb{E}(x)$$

$$\hat{x} = D(\hat{h})$$



# Concentrated class tag

U-net



$$\begin{aligned} W_x &= W_y \\ H_x &= H_y \end{aligned}$$