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- Previous assignments
- The Mini-Project
- Introduction
- Convolution
- Convolutional Neural Networks
 - The Convolution Layer
 - The Pooling Layer
 - Regularization
 - Examples
- Transfer learning
- Practical Methodology

Machine learning – Block 4

Måns Magnusson
Department of Statistics, Uppsala University

Autumn 2022



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- Previous assignments
 - The Mini-Project and Master Thesis Projects
 - Convolutional Neural Networks
 - Transfer Learning



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-
- A little too simple?
 - Problems with Tensorflow and R



On this weeks assignment

- Previous assignments
 - The Mini-Project
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- It takes long time to run the models this week. Start early!





Mini-project

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- Time to start think about the project.



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Mini-project

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- **Supervised problem of choice on real data.**



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Mini-project

- Time to start think about the project.
- **Supervised problem of choice on real data.**
- 2-3 students.



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Mini-project

- Time to start think about the project.
- **Supervised problem of choice on real data.**
- 2-3 students.
- Supply a **project proposal** of data and problem at the end of *15th of December 23.59*.
- *Hint!* Submit page 1-1.5 of the project as project proposal.
- Deadline is after all lectures on supervised learning



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- Feel free to combine it with your master thesis project!



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- *Hint!* Submit page 1-1.5 of the project as project proposal.
- Deadline is after all lectures on supervised learning
- Feel free to combine it with your master thesis project!
- Check with me if you have questions.
- The project should result in a 4 page report (PDF) using the **ICML LaTeX template**.



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Section 3

Introduction



Convolutional Neural Networks

- Acknowledgements: Anders Eklund, Linköping University.

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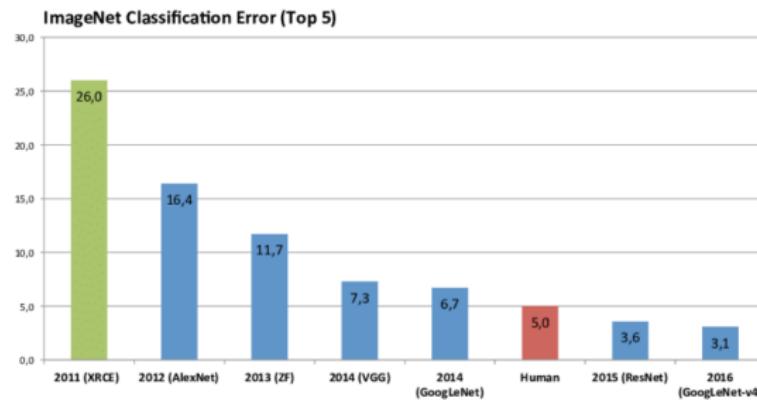


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Convolutional Neural Networks

- **Acknowledgements:** Anders Eklund, Linköping University.
- **Convolutional** Neural Networks are behind great progress in the 2010s.
- It has revolutionized **Computer Vision**.
- Also called: ConvNets, Convolutional nets, Convolutional networks

Figure: ImageNet performance (Roessler, 2019)



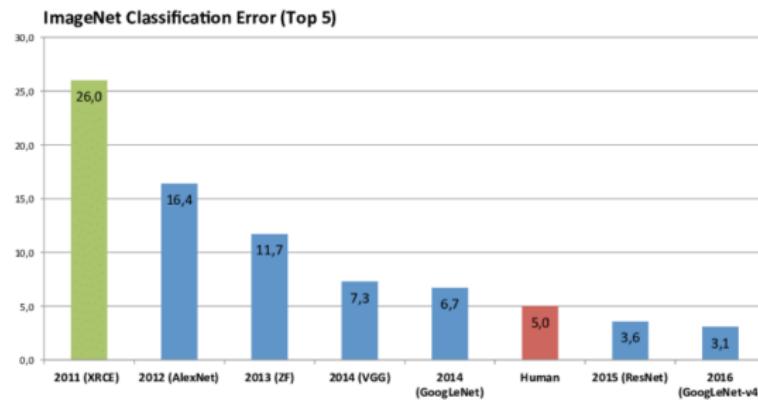


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- Special architecture that works well for data with a **grid structure**
 1. 1D-grids: Time series



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- Special architecture that works well for data with a **grid structure**
 1. 1D-grids: Time series
 2. 2D-grids: Gray-scale Images (pixels)



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- Special architecture that works well for data with a **grid structure**
 1. 1D-grids: Time series
 2. 2D-grids: Gray-scale Images (pixels)
 3. 3D-grids: Color Images (pixels and channels)



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 1. 1D-grids: Time series
 2. 2D-grids: Gray-scale Images (pixels)
 3. 3D-grids: Color Images (pixels and channels)
 4. 4D-grids: Color Video (pixels, channels, frames)



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- Problems
 - Image Classification



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- Problems
 - Image Classification
 - Image Segmentation



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Computer Vision

- Problems
 - Image Classification
 - Image Segmentation
 - Object Detection



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Computer Vision

● Problems

- Image Classification
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- Problems
 - Image Classification
 - Image Segmentation
 - Object Detection
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- **Focus:** 2D and 3D data



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Computer Vision

- **Problems**
 - Image Classification
 - Image Segmentation
 - Object Detection
 - Object Localization
- **Focus:** 2D and 3D data
- **Very Large Datasets:**
 - ImageNet: 14M Images, 20k classes, 1M bounding boxes



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Computer Vision

- **Problems**
 - Image Classification
 - Image Segmentation
 - Object Detection
 - Object Localization
- **Focus:** 2D and 3D data
- **Very Large Datasets:**
 - ImageNet: 14M Images, 20k classes, 1M bounding boxes
 - Many different pre-trained models (e.g. VGG16)



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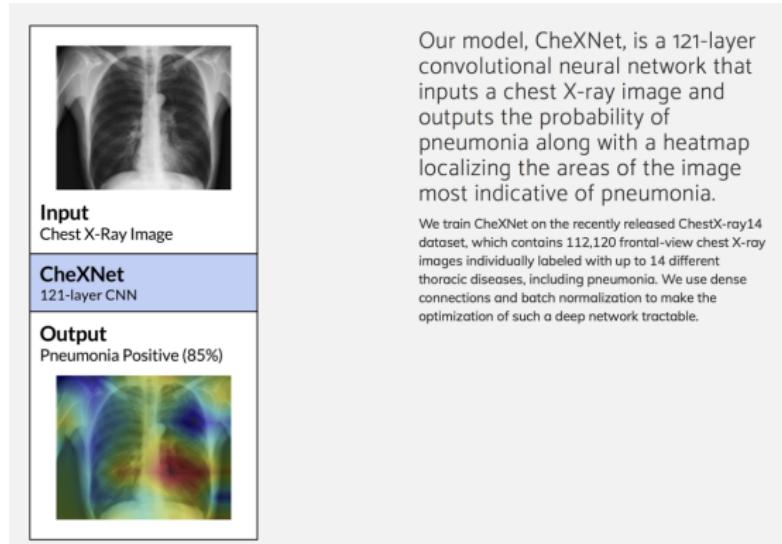
Figure: Object detection (see
<https://www.youtube.com/watch?v=VOC3huqHrss>)



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Example: Pneumonia detection



Our model, CheXNet, is a 121-layer convolutional neural network that inputs a chest X-ray image and outputs the probability of pneumonia along with a heatmap localizing the areas of the image most indicative of pneumonia.

We train CheXNet on the recently released ChestX-ray14 dataset, which contains 112,120 frontal-view chest X-ray images individually labeled with up to 14 different thoracic diseases, including pneumonia. We use dense connections and batch normalization to make the optimization of such a deep network tractable.

Figure: Rajpurkar et al. (2017). Chexnet: Radiologist-level pneumonia detection on chest x-rays with deep learning. arXiv preprint arXiv:1711.05225.



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Example: Fracture detection



Figure 1. 2 images from the dataset. The area within the red box is the section presented to the network in order to classify the image. The left image is of a wrist fracture while the right image is without any apparent fracture.

Figure: Olczak et al, (2017) Artificial intelligence for analyzing orthopedic trauma radiographs, Acta Orthopaedica, 88:6, 581-586



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What is an Image?

- 2-dimensional object
- Each pixel has:
 1. a coordinate
 2. a value (light intensity)



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- **Grayscale:** single channel
- **Color:** three channel (RGB)



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What is an Image?

- 2-dimensional object
- Each pixel has:
 1. a coordinate
 2. a value (light intensity)
- **Grayscale:** single channel
- **Color:** three channel (RGB)
- Spatial and hierarchical correlation structures



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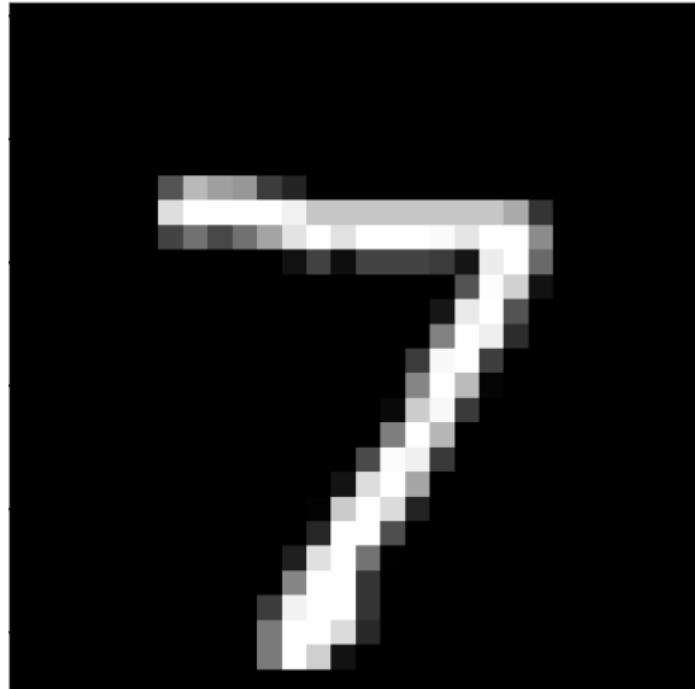


Figure: Example from the MNIST dataset (28 by 28 pixels)



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How to train models for images?

- We want to learn **representations** of parts of images

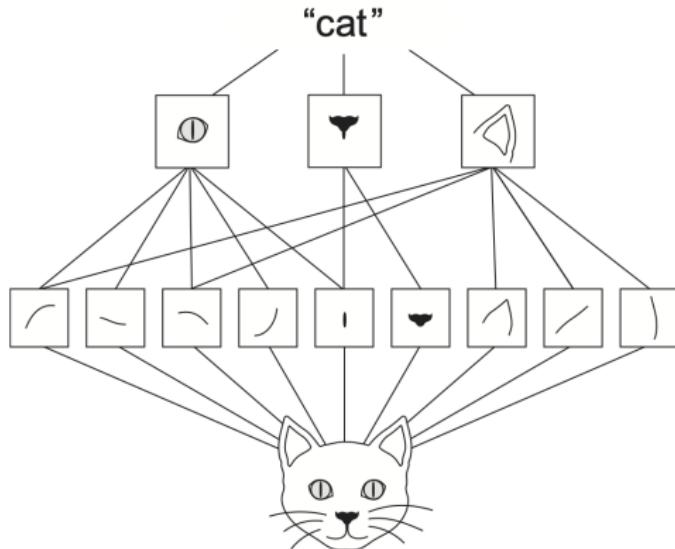


Figure: The representations of a cat (Chollet and Allair, 2018, Fig 5.2)



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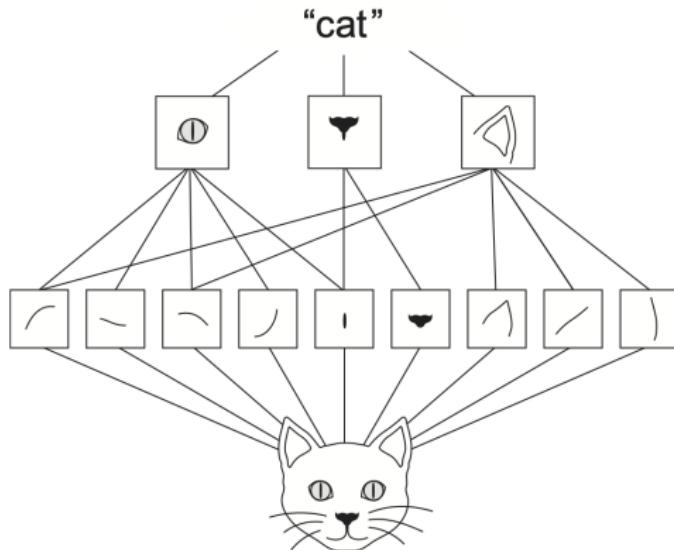


Figure: The representations of a cat (Chollet and Allair, 2018, Fig 5.2)

- CNN uses **Convolutional Layers** to learn **parameter efficient** representations



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Learning Representations for Images (again)

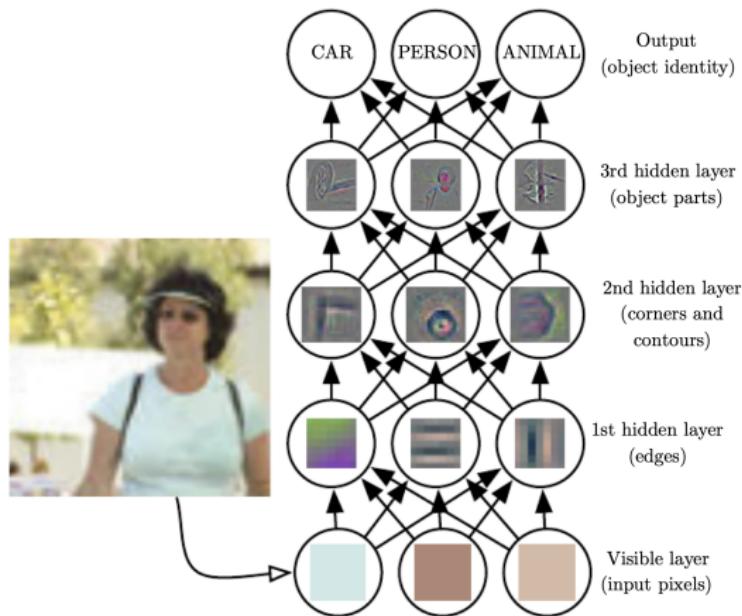


Figure: Learning representations for images (Goodfellow et al, 2017, Fig. 1.2)



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Section 4

Convolution



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Convolution

- Different definitions are common, one example:

$$y(t) = \int x(\tau)k(t - \tau)d\tau = (x * k)(t)$$

- Intuition: "Weighting together two functions"
- In a convolutional layer:

1. $x(t)$: Input
2. $k(t)$: Kernel, filter, "feature"
3. $y(t)$: Output, feature map



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Discrete Convolution

- If t is discrete (as in a grid):

$$y(t) = (x * k)(t) = \sum_{\tau=-\infty}^{\infty} x(\tau)k(t-\tau)$$

- In the case of images we have 2 discrete dimensions

$$Y(i, j) = (X * K) \sum_m \sum_n X(m, n)K(i - m, j - n)$$

- Sometimes the cross-correlation is called convolution:

$$Y(i, j) = (X * K) \sum_m \sum_n X(m, n)K(i + m, j + n)$$

1. $X(i, j)$: Input (2D)
2. $K(i, j)$: Kernel, filter, "feature" (2D)
3. $Y(i, j)$: Output, feature map (2D)



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Convolution of Images: 2D

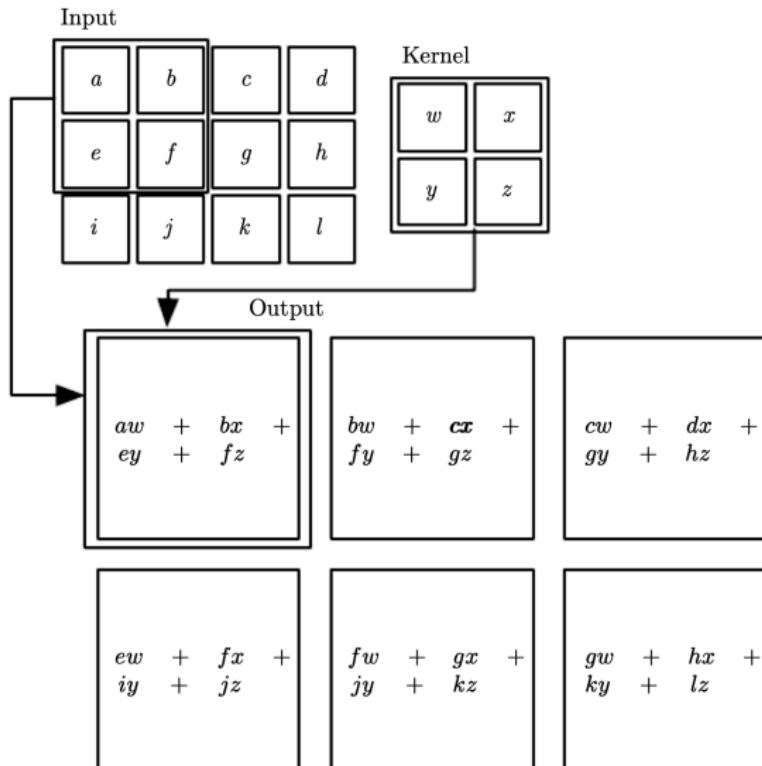


Figure: Convolution for an Image (Goodfellow et al, 2017, Fig. 9.1)



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Convolution of images: Example

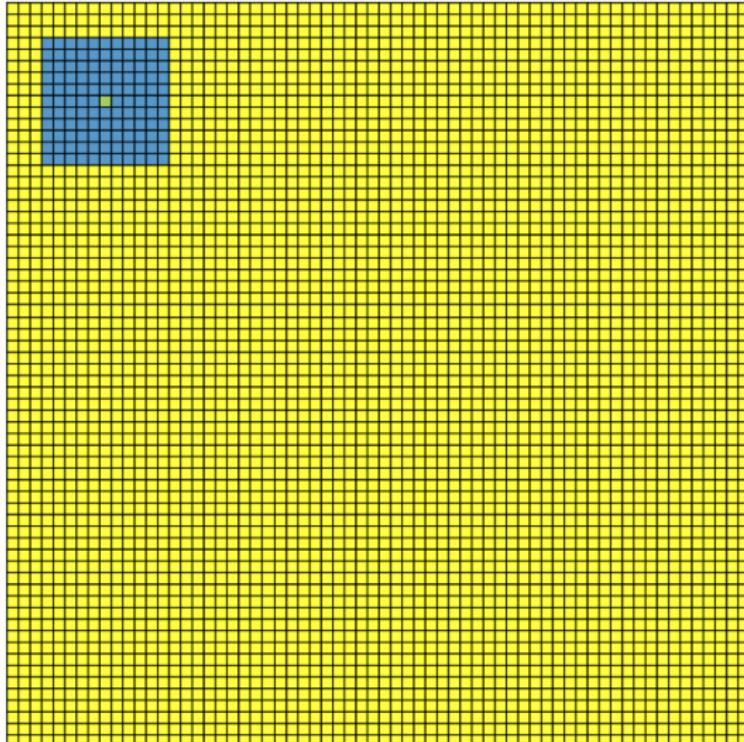


Figure: Convolution example.



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Convolution of images: Examples

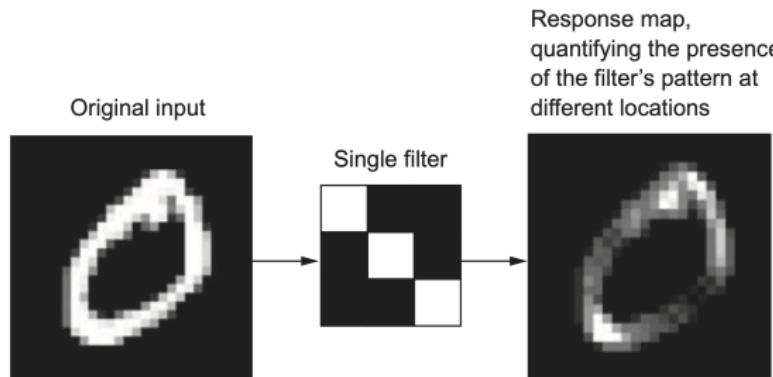


Figure: Convolution for an Image (Chollet and Allaire, 2018, Fig. 5.3)



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$$X = \begin{bmatrix} 0 & 0 & 0 & 1 & 1 \\ 0 & 0 & 0 & 1 & 1 \\ 0 & 0 & 0 & 1 & 1 \\ 0 & 0 & 1 & 1 & 1 \end{bmatrix}, K = \begin{bmatrix} -1 & 1 \\ -1 & 1 \end{bmatrix}$$



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Convolution of images: Example

$$X = \begin{bmatrix} 0 & 0 & 0 & 1 & 1 \\ 0 & 0 & 0 & 1 & 1 \\ 0 & 0 & 0 & 1 & 1 \\ 0 & 0 & 1 & 1 & 1 \end{bmatrix}, K = \begin{bmatrix} -1 & 1 \\ -1 & 1 \end{bmatrix}$$

$$Y = \begin{bmatrix} 0 & 0 & 2 & 0 \\ 0 & 0 & 2 & 0 \\ 0 & 1 & 2 & 0 \end{bmatrix},$$



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Section 5

Convolutional Neural Networks



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Convolutional Neural Networks

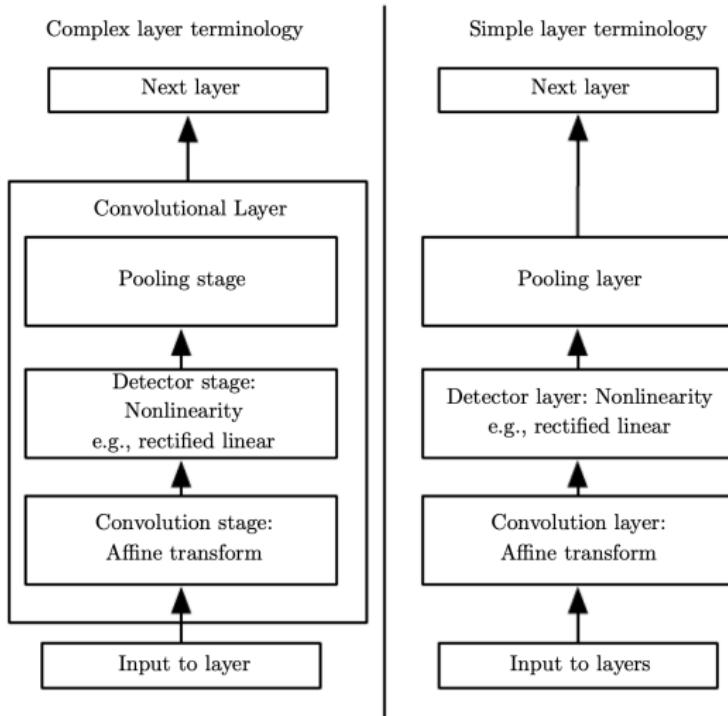


Figure: Convolution layer (Goodfellow et al, 2018, Fig. 9.7)



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Convolutional Neural Networks

- Most convolutional neural networks have:
 1. Many convolutional layers
 2. More kernels higher up in the network
 3. A classification head (usually a feed-forward neural network)



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- Benefits:
 1. Few(er) parameters (filters)
 2. Captures **local structures**
 3. Efficient computations



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- How to choose filters?
 1. Before: **manually handcrafted**



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- Benefits:
 1. Few(er) parameters (filters)
 2. Captures **local structures**
 3. Efficient computations
- How to choose filters?
 1. Before: **manually handcrafted**
 2. Now: **learn the filters**



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Convolution layer

- **Input:** Data or Feature Maps



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Convolution layer

- **Input:** Data or Feature Maps
- **Parameters:**
 - N filters/kernels of size $m \times m$
 - N bias terms (one per filter)



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- **Input:** Data or Feature Maps
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 - N filters/kernels of size $m \times m$
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- **Activation functions:** Applied element wise on feature maps



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- **Output:** Feature Maps



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Convolution layer

- **Input:** Data or Feature Maps
- **Parameters:**
 - N filters/kernels of size $m \times m$
 - N bias terms (one per filter)
- **Activation functions:** Applied element wise on feature maps
- **Output:** Feature Maps
- In Keras:
`layer_conv_2d(filters = 32, kernel_size = c(3,3), activation = "relu", input_shape = c(32,32,3))`



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Padding

- Handling edges
- *Padding*: add 0 around the image
- Necessary to **keep size** of feature maps



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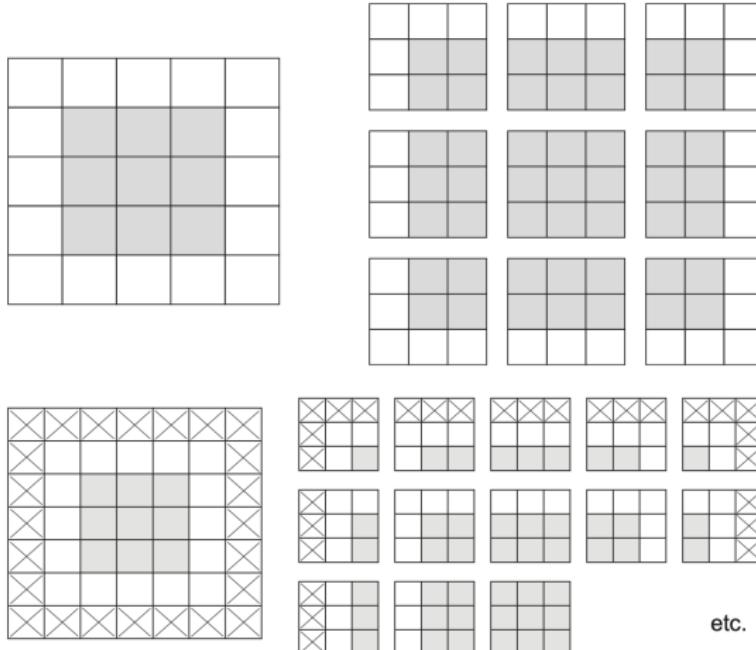


Figure: Padding and valid edge handling (Chollet and Allair (2018), Fig. 5.5, 5.6)



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Stride

- Skip every n th pixel
- Reduces the computations

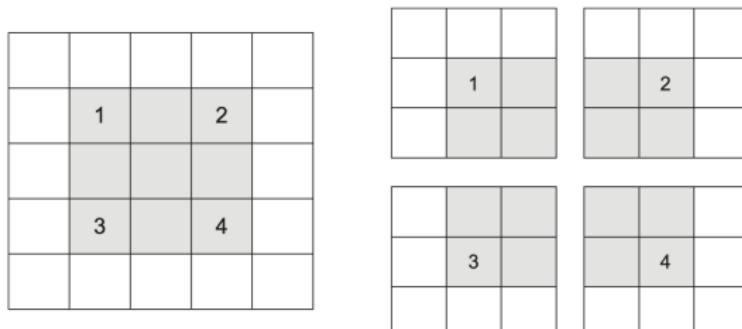


Figure: Strides (Chollet and Allair (2018), Fig. 5.5, 5.6)



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Why Convolution Layers?

- Captures local spatial structure
- Reduces the number of parameters (parameter sharing)
 1. The number and size of filters
 2. We use the same filters everywhere



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Why Convolution Layers?

- Captures local spatial structure
- Reduces the number of parameters (parameter sharing)
 1. The number and size of filters
 2. We use the same filters everywhere
- Example: a 1 megapixel image (1000×1000 pixels)
 1. Dense network with 100 nodes: **100M** parameters
 2. CNN network with 100 3×3 filters: **1000** parameters (900 from filters, 100 bias terms)



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Convolution Neural Nets

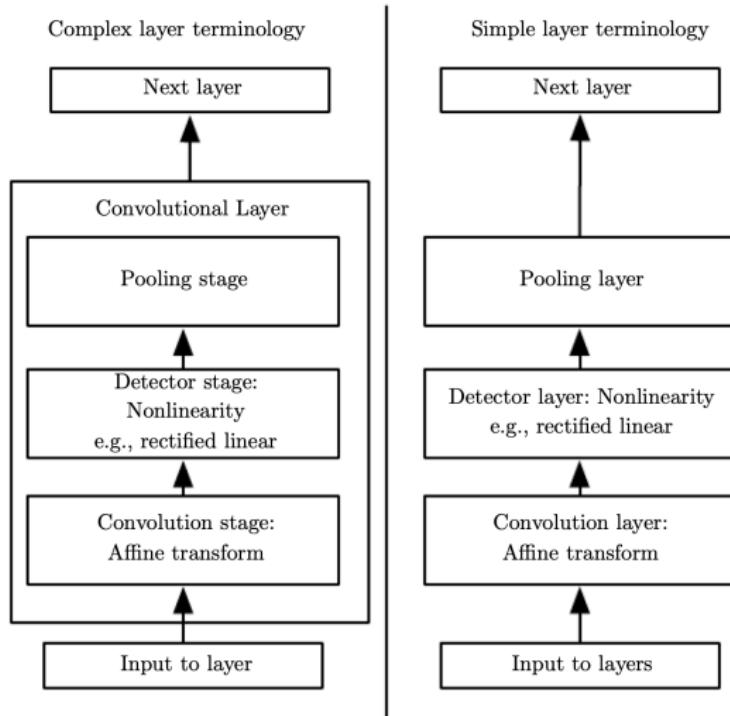


Figure: Convolution layer (Goodfellow et al, 2018, Fig. 9.7)



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Detector stage

- Remember, in feed-forward networks: $\mathbf{h} = \sigma(\mathbf{XW} + b)$
- In CNN:
 1. \mathbf{W} is the filter



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Detector stage

- Remember, in feed-forward networks: $\mathbf{h} = \sigma(\mathbf{XW} + b)$
- In CNN:
 1. \mathbf{W} is the filter
 2. \mathbf{X} is the input feature map



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Detector stage

- Remember, in feed-forward networks: $\mathbf{h} = \sigma(\mathbf{XW} + b)$
- In CNN:
 1. \mathbf{W} is the filter
 2. \mathbf{X} is the input feature map
 3. \mathbf{XW} is the convolutional feature map



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Detector stage

- Remember, in feed-forward networks: $\mathbf{h} = \sigma(\mathbf{XW} + b)$
- In CNN:
 1. \mathbf{W} is the filter
 2. \mathbf{X} is the input feature map
 3. \mathbf{XW} is the convolutional feature map
 4. b is a bias (one per filter)



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Detector stage

- Remember, in feed-forward networks: $\mathbf{h} = \sigma(\mathbf{XW} + b)$
- In CNN:
 1. \mathbf{W} is the filter
 2. \mathbf{X} is the input feature map
 3. \mathbf{XW} is the convolutional feature map
 4. b is a bias (one per filter)
 5. σ is the activation function (usually a ReLU)



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 - **The Pooling Layer**
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- We take a function f that return one value per pooling kernel



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Pooling layer

- We take a function f that return one value per pooling kernel
- Most commonly $f = \max$
- Commonly a 2×2 pooling kernel with stride 2
- **Why?** Reduce the size of feature map, but keep the activation



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Pooling layer

- We take a function f that return one value per pooling kernel
- Most commonly $f = \max$
- Commonly a 2×2 pooling kernel with stride 2
- **Why?** Reduce the size of feature map, but keep the activation
- In Keras:
`layer_max_pooling_2d(pool_size = c(2, 2))(`



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Max Pooling

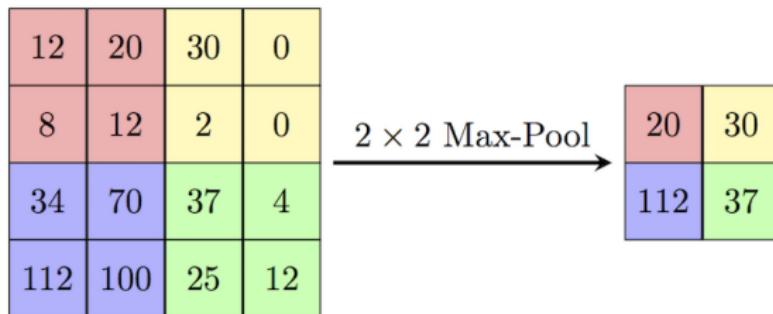


Figure: Strides (Computer Science Wikipedia)



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Using pooling to learn invariances

- pooling over spatial positions: invariant to translation
- pooling over different filters: invariant to transformations

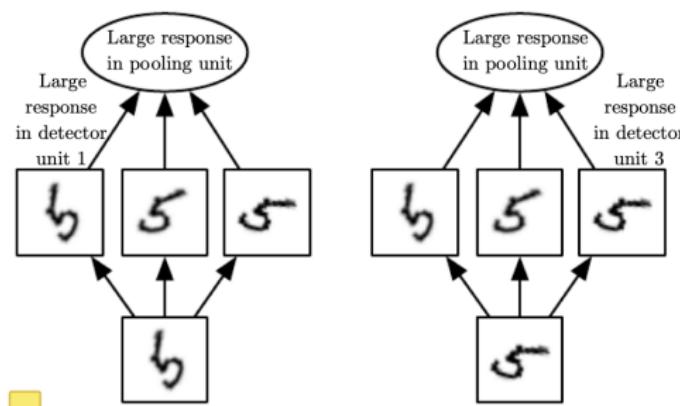


Figure: Learning invariances (Goodfellow et al., 2017, Fig. 9.9)



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Data Augmentation



Figure: Data Augmentation (Chollet and Allair, 2018, Fig 5.10)



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Data Augmentation



Figure: Data Augmentation (Chollet and Allair, 2018, Fig 5.10)

- Can be done directly in Keras (data generator)



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-
- AlexNet (2012), 5 convolutional layers
 - VGG16 (2014), 16 convolutional layers
 - ResNet (2015), 152 convolutional layers



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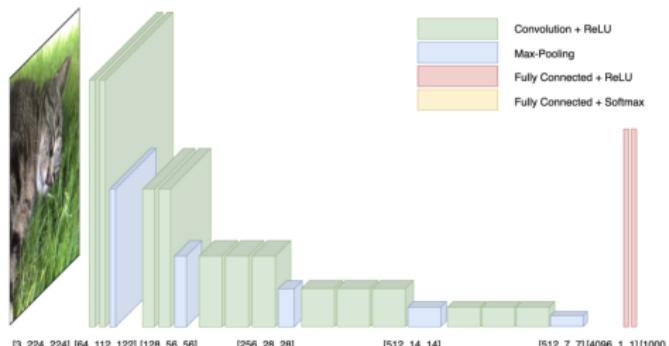


Figure 2.4: Illustration of the data flow through the network VGG16. Data size, of the format $[c, h, w]$, is shown for the input image, output of each max-pooling layer, output after the first two fully connected layers, and the final network output.

Jesper Westell, Multi-Task Learning using Road Surface Condition Classification and Road Scene Semantic Segmentation, LIU-IMT-TFK-A-19/570-SE



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Section 6

Transfer learning



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Transfer learning

- "Transfer knowledge between problems"
- In practice: Transfer/reuse learned weights



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Transfer learning

- "Transfer knowledge between problems"
- In practice: Transfer/reuse learned weights
- A Bayesian perspective: A strong prior
- Commonly: Use (large) pre-trained models for smaller problems
- One of the main reasons for the success of (convolutional) neural networks



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Transfer learning

- "Transfer knowledge between problems"
- In practice: Transfer/reuse learned weights
- A Bayesian perspective: A strong prior
- Commonly: Use (large) pre-trained models for smaller problems
- One of the main reasons for the success of (convolutional) neural networks
- Two types of transfer learning:
 - Feature extraction
 - Fine Tuning



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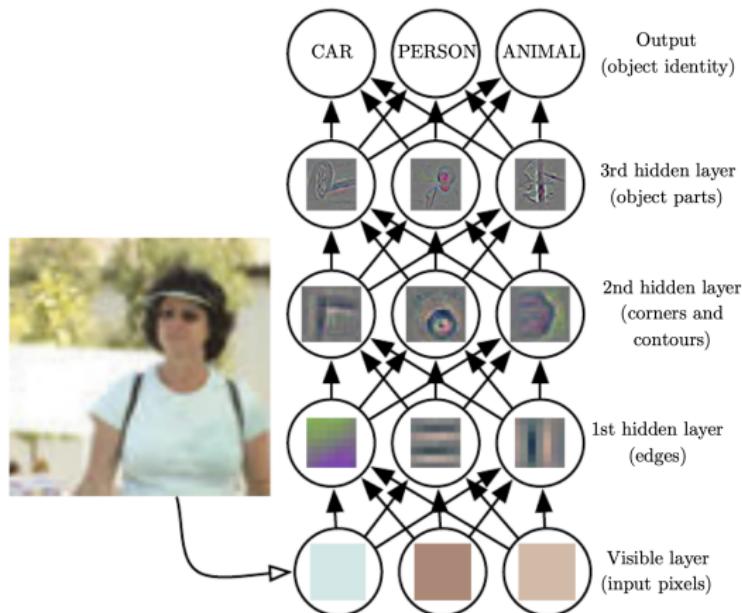


Figure: Learning representations can be crucial (Goodfellow et al, 2017, Fig. 1.2)



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Feature Extraction

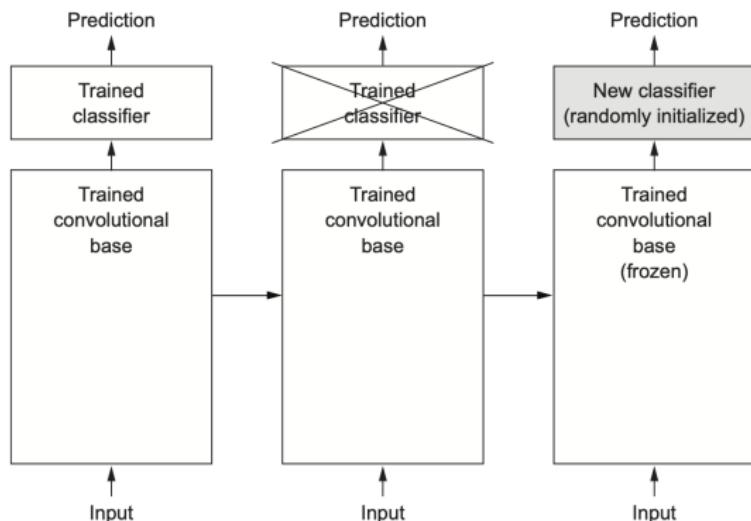


Figure: Using convnets as base for feature extraction (Chollet and Allair, 2018, Fig 5.12)



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Fine-Tuning

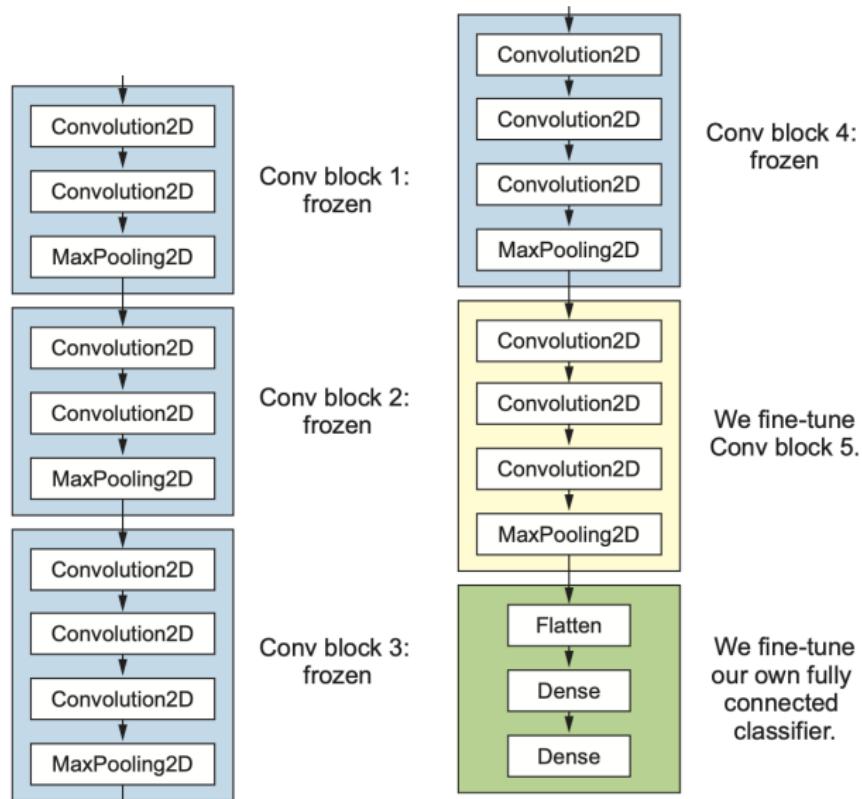


Figure: Finetuning a convolutional base (Chollet and Allair, 2018,
Fig 5.15)



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Section 7

Practical Methodology



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Practical Methodology

1. Determine your goals
2. Setup your baseline
(establish a working end-to-end pipeline as soon as possible)
3. Diagnose your networks performance
4. Make incremental improvements



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1. Determine your goals

- Why are you building a model?



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1. Determine your goals

- Why are you building a model?
- Set up the metric based on the overall target of the system! This may need multiple metrics.



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1. Determine your goals

- Why are you building a model?
- Set up the metric based on the overall target of the system! This may need multiple metrics.
- What is good enough? Remember the **Bayes error!**



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1. Determine your goals

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- Set up the metric based on the overall target of the system! This may need multiple metrics.
- What is good enough? Remember the **Bayes error!**
- What performance can you expect?



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- Some errors are worse than others, e.g. spam filters.



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- What performance can you expect?
- Some errors are worse than others, e.g. spam filters.
- Handling of uncertain predictions?
- **Coverage:** How large proportions can the system predict?



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1. Determine your goals

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- What is good enough? Remember the **Bayes error!**
- What performance can you expect?
- Some errors are worse than others, e.g. spam filters.
- Handling of uncertain predictions?
- **Coverage:** How large proportions can the system predict?
- It is not uncommon that manual curation is faster and easier in some settings.



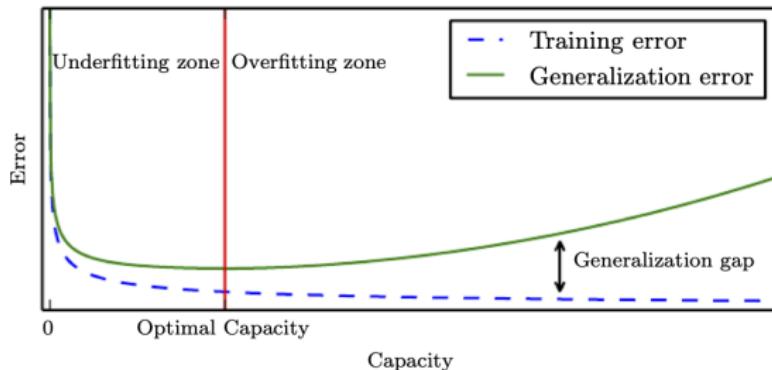
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-
- Start with the most simple possible model (logistic regression)
 - Start from previous approaches
 - Start with a simple neural network that is common in the domain/defaults (CNN for images, Adam as optimizer)



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Statistical Learning Theory

Figure: Test, training, and model complexity (Goodfellow et al, 2017, Figure 5.3)





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3. Diagnosing and improving your model: More data

- Gather more data: Usually a good solution
- Avoid focus on the "best" algorithm and the "ML-sickness"
- If high loss in training: The training data is not yet used fully
- If high loss on test: The quality of the training data can be poor. This means that the Bayes error is larger.
- If low training error, but high test error: Probably more data is a good way forward. If costly or difficult with more data -*i.e.* regularization



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Learning curve to assess if you need more data

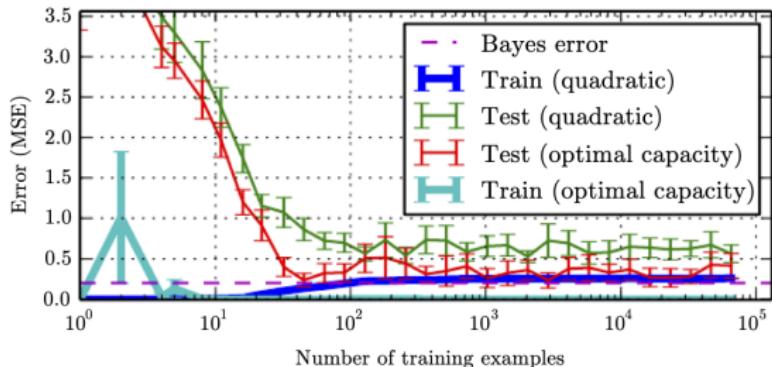


Figure: Learning curve to assess the need for more data (Goodfellow et al., 2017, Fig 5.4)



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3. Diagnosing and improving your model: Regularization

- General idea: Increase data and model capacity until target is reached.
- Adapt hyperparameters to get **optimal capacity**
- Goal: The primary goal of manual hyperparameter search is to adjust the effective capacity of the model to match the complexity of the task.
- Ideally, each marginal hyperparameter has a U-shaped form
- Step 1: Get good training error. Tune learning rate.
U-shaped for training error. Neural network performs best when training error is low.
- Step 2: Tuning hyperparameters (regularization) requires monitoring both training and test error to diagnose whether your model is overfitting or underfitting
- Best performance: Larger model that is regularized well.
- End goal: Good performance on test set
- With low training error you can always improve by adding more data



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Hyper-parameter optimization

- Neural networks has many hyperparameters
- What is a hyperparameter in a neural network?
- Grid search:
 - Setup a grid of potential values
 - For 1-4 hyperparameter: grid search can work well
 - Usually iterative/repeated grid search is best: start with three values, and work iteratively
 - Grows exponentially with the number of parameters
- Random search
 - Specify a marginal distribution for each hyperparameter (additional work)
 - Common: uniform on log scale
 - Can also be done iteratively
 - random search can be exponentially more efficient
 - reduce the error faster