Neural network

Machine Learning II

Lecture 3-a

THE GEORGE WASHINGTON UNIVERSITY

WASHINGTON, DC

Taylor series expansion

$$
\begin{aligned}
F(x) = F(x^*) &+ \frac{d}{dx}F(x)\Big|_{x=x^*}(x-x^*) \\
&+ \frac{1}{2}\frac{d^2}{dx^2}F(x)\Bigg|_{x=x^*}(x-x^*)^2 + \cdots \\
&+ \frac{1}{n!}\frac{d^n}{dx^n}F(x)\Bigg|_{x=x^*}(x-x^*)^n + \cdots
\end{aligned}
$$

Example

$$F(x) = e^{-x}$$

Taylor series of $F(x)$ about $x^* = 0$:

$$F(x) = e^{-x} = e^{-0} - e^{-0}(x-0) + \frac{1}{2}e^{-0}(x-0)^2 - \frac{1}{6}e^{-0}(x-0)^3 + \dots$$

$$F(x) = 1 - x + \frac{1}{2}x^2 - \frac{1}{6}x^3 + \dots$$

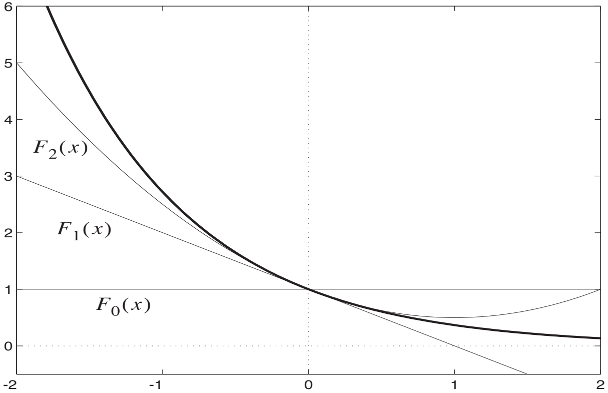
Taylor series approximations:

$$F(x) \approx F_0(x) = 1$$

$$F(x) \approx F_1(x) = 1 - x$$

$$F(x) \approx F_2(x) = 1 - x + \frac{1}{2}x^2$$

Plot of approximations



Vector case

$$F(\mathbf{x}) = F(x_1, x_2, \dots, x_n)$$

$$\begin{aligned}
F(\mathbf{x}) = F(\mathbf{x}^*) &+ \frac{\partial}{\partial x_1} F(\mathbf{x})\bigg|_{\mathbf{x}=\mathbf{x}^*}(x_1 - x_1^*) + \frac{\partial}{\partial x_2} F(\mathbf{x})\bigg|_{\mathbf{x}=\mathbf{x}^*}(x_2 - x_2^*) \\
&+ \cdots + \frac{\partial}{\partial x_n} F(\mathbf{x})\bigg|_{\mathbf{x}=\mathbf{x}^*}(x_n - x_n^*) + \frac{1}{2}\frac{\partial^2}{\partial x_1^2} F(\mathbf{x})\bigg|_{\mathbf{x}=\mathbf{x}^*}(x_1 - x_1^*)^2 \\
&+ \frac{1}{2}\frac{\partial^2}{\partial x_1 \partial x_2} F(\mathbf{x})\bigg|_{\mathbf{x}=\mathbf{x}^*}(x_1 - x_1^*)(x_2 - x_2^*) + \cdots
\end{aligned}$$

Matrix form

$$F(\mathbf{x}) = F(\mathbf{x}^*) + \nabla F(\mathbf{x})^T \Big|_{\mathbf{x} = \mathbf{x}^*} (\mathbf{x} - \mathbf{x}^*)$$

$$+ \frac{1}{2}(\mathbf{x} - \mathbf{x}^*)^T \nabla^2 F(\mathbf{x}) \Big|_{\mathbf{x} = \mathbf{x}^*} (\mathbf{x} - \mathbf{x}^*) + \cdots$$

Gradient

$$\nabla F(\mathbf{x}) = \begin{bmatrix} \frac{\partial}{\partial x_1} F(\mathbf{x}) \\ \frac{\partial}{\partial x_2} F(\mathbf{x}) \\ \vdots \\ \frac{\partial}{\partial x_n} F(\mathbf{x}) \end{bmatrix}$$

Hessian

$$\nabla^2 F(\mathbf{x}) = \begin{bmatrix} \frac{\partial^2}{\partial x_1^2} F(\mathbf{x}) & \frac{\partial^2}{\partial x_1 \partial x_2} F(\mathbf{x}) & \ldots & \frac{\partial^2}{\partial x_1 \partial x_\mathrm{n}} F(\mathbf{x}) \\ \frac{\partial^2}{\partial x_2 \partial x_1} F(\mathbf{x}) & \frac{\partial^2}{\partial x_2^2} F(\mathbf{x}) & \ldots & \frac{\partial^2}{\partial x_2 \partial x_\mathrm{n}} F(\mathbf{x}) \\ \vdots & \vdots & & \vdots \\ \frac{\partial^2}{\partial x_\mathrm{n} \partial x_1} F(\mathbf{x}) & \frac{\partial^2}{\partial x_n \partial x_2} F(\mathbf{x}) & \ldots & \frac{\partial^2}{\partial x_n^2} F(\mathbf{x}) \end{bmatrix}$$

Directional derivatives

- First derivative (slope) of $F(\mathbf{x})$ along x_i axis: $\frac{\sigma F(\mathbf{x})}{\sigma x_i}$ - (i th element of gradient).

- Second derivative (curvature) of $F(\mathbf{x})$ along x_i axis: $\frac{\sigma^2 F(\mathbf{x})}{\sigma x_i^2}$ - (i, i th element of Hesian)

- First derivative (slope) of $F(\mathbf{x})$ along $\mathbf{p}$: $\frac{\mathbf{p}^T \nabla F(\mathbf{x})}{||\mathbf{p}}$

- Second derivative (curvature) of $F(\mathbf{x})$ along $\mathbf{p}$: $\frac{\mathbf{p}^T \nabla^2 F(\mathbf{x})}{||\mathbf{p}^2}$

Example

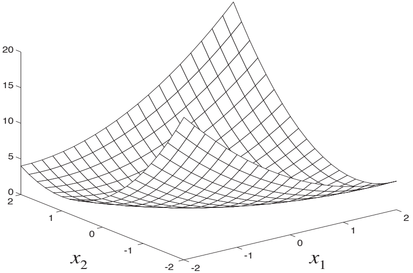
$$F(\mathbf{x}) = x_1^2 + 2x_1x_2 + 2x_2^2$$

$$\mathbf{x}^* = \begin{bmatrix} 0.5 \\ 0 \end{bmatrix} \qquad \mathbf{p} = \begin{bmatrix} 1 \\ -1 \end{bmatrix}$$

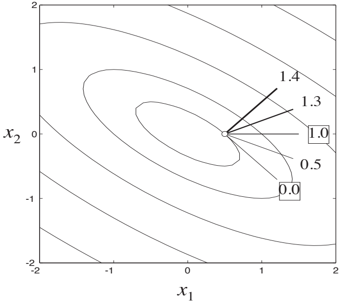
$$\nabla F(\mathbf{x})\Big|_{\mathbf{x} = \mathbf{x}^*} = \left.\begin{bmatrix} \dfrac{\partial}{\partial x_1}F(\mathbf{x}) \\ \dfrac{\partial}{\partial x_2}F(\mathbf{x}) \end{bmatrix}\right|_{\mathbf{x} = \mathbf{x}^*} = \left.\begin{bmatrix} 2\mathrm{x}_1 + 2\mathrm{x}_2 \\ 2\mathrm{x}_1 + 4\mathrm{x}_2 \end{bmatrix}\right|_{\mathbf{x} = \mathbf{x}^*} = \begin{bmatrix} 1 \\ 1 \end{bmatrix}$$

$$\frac{\mathbf{p}^T \nabla F(\mathbf{x})}{\|\mathbf{p}\|} = \frac{\begin{bmatrix} 1 & -1 \end{bmatrix}\begin{bmatrix} 1 \\ 1 \end{bmatrix}}{\left\|\begin{bmatrix} 1 \\ -1 \end{bmatrix}\right\|} = \frac{\begin{bmatrix} 0 \end{bmatrix}}{\sqrt{2}} = 0$$

Plots



Directional Derivatives



Minima

Strong Minimum:

- The point $\mathbf{x}^*$ is a strong minimum of $F(\mathbf{x})$ if a scalar $\delta > 0$ exists, such that $F(\mathbf{x}^*) < F(\mathbf{x}^* + \Delta\mathbf{x})$ such that $\delta > ||\Delta\mathbf{x}|| > 0$.

Global Minimum:

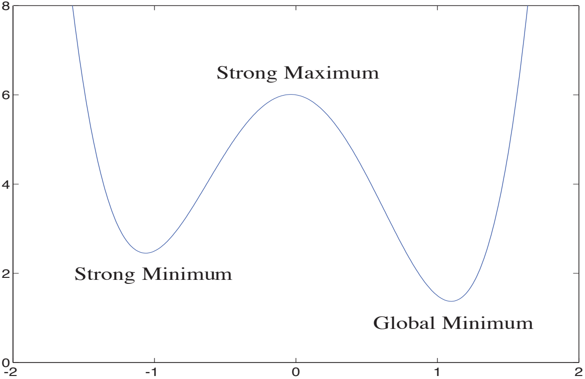
- The point $\mathbf{x}^*$ is a unique global minimum of $F(\mathbf{x})$ if $F(\mathbf{x}^*) < F(\mathbf{x}^* + \Delta\mathbf{x})$ for all $\Delta\mathbf{x} \neq 0$.

Weak Minimum:

- The point $\mathbf{x}^*$ is a weak minimum of $F(\mathbf{x})$ if it is not a strong minimum, and scalar $\delta > 0$ exists such that $F(\mathbf{x}^*) \leq F(\mathbf{x}^* + \Delta\mathbf{x})$ for all $\Delta\mathbf{x}$ such that $\delta > ||\Delta\mathbf{x}|| > 0$.

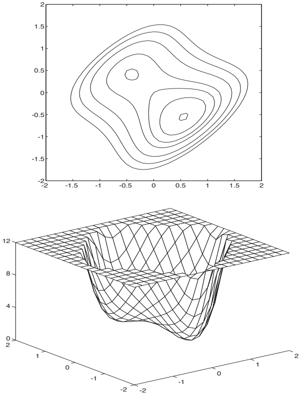
Scalar example

$$F(x) \;=\; 3x^4 - 7x^2 - \frac{1}{2}x + 6$$

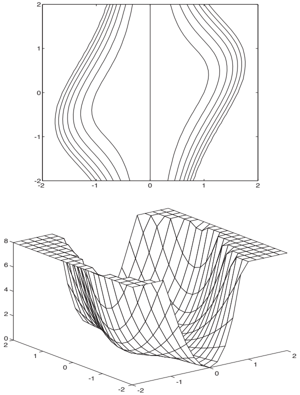


Vector Example

$$F(\mathbf{x}) = (x_2 - x_1)^4 + 8x_1x_2 - x_1 + x_2 + 3$$



$$F(\mathbf{x}) = (x_1^2 - 1.5x_1x_2 + 2x_2^2)x_1^2$$



Example

$$F(\mathbf{x}) = x_1^2 + 2x_1x_2 + 2x_2^2 + x_1$$

$$\nabla F(\mathbf{x}) = \begin{bmatrix} 2x_1 + 2x_2 + 1 \\ 2x_1 + 4x_2 \end{bmatrix} = \mathbf{0} \quad \Longrightarrow \quad \mathbf{x}^* = \begin{bmatrix} -1 \\ 0.5 \end{bmatrix}$$

$$\nabla^2 F(\mathbf{x}) = \begin{bmatrix} 2 & 2 \\ 2 & 4 \end{bmatrix}$$

(Not a function of $\mathbf{x}$ in this case.)

To test the definiteness, check the eigenvalues of the Hessian. If the eigenvalues are all greater than zero, the Hessian is positive definite.

$$\left|\nabla^2 F(\mathbf{x}) - \lambda\mathbf{I}\right| = \left|\begin{bmatrix} 2-\lambda & 2 \\ 2 & 4-\lambda \end{bmatrix}\right| = \lambda^2 - 6\lambda + 4 = (\lambda - 0.76)(\lambda - 5.24)$$

$\lambda = 0.76, 5.24$ Both eigenvalues are positive, therefore strong minimum.

Quadratic functions

$$F(\mathbf{x}) = \frac{1}{2}\mathbf{x}^T\mathbf{A}\mathbf{x} + \mathbf{d}^T\mathbf{x} + c \qquad \text{(Symmetric } \mathbf{A}\text{)}$$

Gradient and Hessian:

Useful properties of gradients:

$$\nabla(\mathbf{h}^T\mathbf{x}) = \nabla(\mathbf{x}^T\mathbf{h}) = \mathbf{h}$$

$$\nabla\mathbf{x}^T\mathbf{Q}\mathbf{x} = \mathbf{Q}\mathbf{x} + \mathbf{Q}^T\mathbf{x} = 2\mathbf{Q}\mathbf{x} \quad \text{(for symmetric } \mathbf{Q}\text{)}$$

Gradient of Quadratic Function:

$$\boxed{\nabla F(\mathbf{x}) = \mathbf{A}\mathbf{x} + \mathbf{d}}$$

Hessian of Quadratic Function:

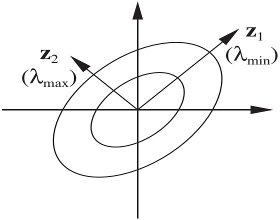
$$\boxed{\nabla^2 F(\mathbf{x}) = \mathbf{A}}$$

Eigenvector

$$\mathbf{p} = \mathbf{z}_{max} \qquad \mathbf{c} = \mathbf{B}^T\mathbf{p} = \mathbf{B}^T\mathbf{z}_{max} = \begin{bmatrix} 0 \\ 0 \\ \vdots \\ 0 \\ 1 \\ 0 \\ \vdots \\ 0 \end{bmatrix}$$

$$\frac{\mathbf{z}_{max}{}^T\mathbf{A}\mathbf{z}_{max}}{\left\|\mathbf{z}_{max}\right\|^2} = \frac{\sum_{i=1}^{n}\lambda_i c_i^2}{\sum_{i=1}^{n} c_i^2} = \lambda_{max}$$

The eigenvalues represent curvature (second derivatives) along the eigenvectors (the principal axes).

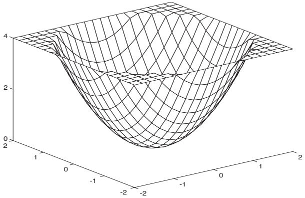


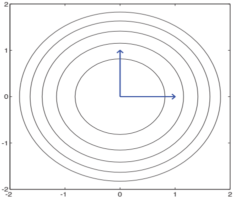
Circular hollow

$$F(\mathbf{x}) = x_1^2 + x_2^2 = \frac{1}{2}\mathbf{x}^T \begin{bmatrix} 2 & 0 \\ 0 & 2 \end{bmatrix} \mathbf{x}$$

$$\nabla^2 F(\mathbf{x}) = \begin{bmatrix} 2 & 0 \\ 0 & 2 \end{bmatrix} \qquad \lambda_1 = 2 \qquad \mathbf{z}_1 = \begin{bmatrix} 1 \\ 0 \end{bmatrix} \qquad \lambda_2 = 2 \qquad \mathbf{z}_2 = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$$

(Any two independent vectors in the plane would work.)

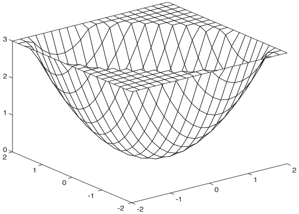


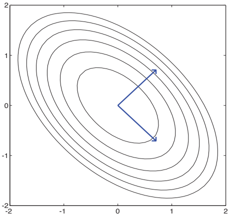


Elliptical hollow

$$F(\mathbf{x}) = x_1^2 + x_1 x_2 + x_2^2 = \frac{1}{2}\mathbf{x}^T \begin{bmatrix} 2 & 1 \\ 1 & 2 \end{bmatrix} \mathbf{x}$$

$$\nabla^2 F(\mathbf{x}) = \begin{bmatrix} 2 & 1 \\ 1 & 2 \end{bmatrix} \qquad \lambda_1 = 1 \qquad \mathbf{z}_1 = \begin{bmatrix} 1 \\ -1 \end{bmatrix} \qquad \lambda_2 = 3 \qquad \mathbf{z}_2 = \begin{bmatrix} 1 \\ 1 \end{bmatrix}$$

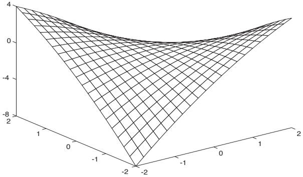


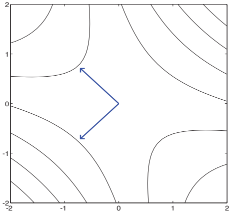


Elongated saddle

$$F(\mathbf{x}) = -\frac{1}{4}x_1^2 - \frac{3}{2}x_1 x_2 - \frac{1}{4}x_2^2 = \frac{1}{2}\mathbf{x}^T\begin{bmatrix}-0.5 & -1.5\\ -1.5 & -0.5\end{bmatrix}\mathbf{x}$$

$$\nabla^2 F(\mathbf{x}) = \begin{bmatrix}-0.5 & -1.5\\ -1.5 & -0.5\end{bmatrix} \qquad \lambda_1 = 1 \qquad \mathbf{z}_1 = \begin{bmatrix}-1\\ 1\end{bmatrix} \qquad \lambda_2 = -2 \qquad \mathbf{z}_2 = \begin{bmatrix}-1\\ -1\end{bmatrix}$$

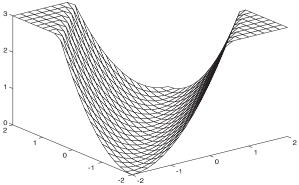


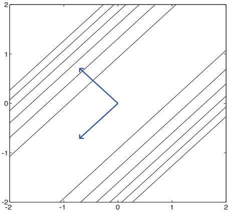


Stationary Valley

$$F(\mathbf{x}) = \frac{1}{2}x_1^2 - x_1 x_2 + \frac{1}{2}x_2^2 = \frac{1}{2}\mathbf{x}^T\begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix}\mathbf{x}$$

$$\nabla^2 F(\mathbf{x}) = \begin{bmatrix} 1 & -1 \\ -1 & 1 \end{bmatrix} \qquad \lambda_1 = 1 \qquad \mathbf{z}_1 = \begin{bmatrix} -1 \\ 1 \end{bmatrix} \qquad \lambda_2 = 0 \qquad \mathbf{z}_2 = \begin{bmatrix} -1 \\ -1 \end{bmatrix}$$





OR solution

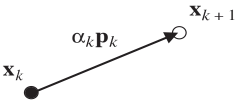
- If the eigenvalues of the Hessian matrix are all positive, the function will have a single strong minimum.
- If the eigenvalues are all negative, the function will have a single strong maximum.
- If some eigenvalues are positive and other eigenvalues are negative, the function will have a single saddle point.
- If the eigenvalues are all nonnegative, but some eigenvalues are zero, then the function will either have a weak minimum or will have no stationary point.
- If the eigenvalues are all nonpositive, but some eigenvalues are zero, then the function will either have a weak maximum or will have no stationary point.
- Stationary point: $\mathbf{x}^* = \mathbf{A}^{-1}\mathbf{d}$

Basic optimization algorithm

$$\boxed{\mathbf{x}_{k+1} = \mathbf{x}_k + \alpha_k \mathbf{p}_k}$$

or

$$\Delta \mathbf{x}_k = (\mathbf{x}_{k+1} - \mathbf{x}_k) = \alpha_k \mathbf{p}_k$$



$\mathbf{p}_k$ - Search Direction

α_k - Learning Rate

Steepest descent

Choose the next step so that the function decreases:

$$F(\mathbf{x}_{k+1}) < F(\mathbf{x}_k)$$

For small changes in $\mathbf{x}$ we can approximate $F(\mathbf{x})$:

$$F(\mathbf{x}_{k+1}) = F(\mathbf{x}_k + \Delta\mathbf{x}_k) \approx F(\mathbf{x}_k) + \mathbf{g}_k^T \Delta\mathbf{x}_k$$

where

$$\mathbf{g}_k \equiv \nabla F(\mathbf{x}) \Big|_{\mathbf{x} = \mathbf{x}_k}$$

If we want the function to decrease:

$$\mathbf{g}_k^T \Delta\mathbf{x}_k = \alpha_k \mathbf{g}_k^T \mathbf{p}_k < 0$$

We can maximize the decrease by choosing:

$$\mathbf{p}_k = -\mathbf{g}_k$$

$$\boxed{\mathbf{x}_{k+1} = \mathbf{x}_k - \alpha_k \mathbf{g}_k}$$

Example

$$F(\mathbf{x}) = x_1^2 + 2x_1x_2 + 2x_2^2 + x_1$$

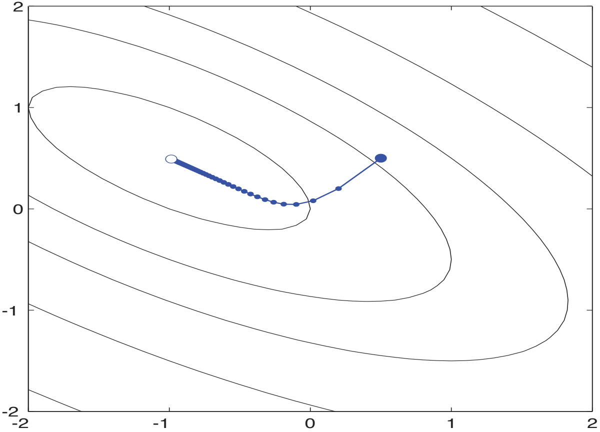
$$\mathbf{x}_0 = \begin{bmatrix} 0.5 \\ 0.5 \end{bmatrix} \qquad \alpha = 0.1$$

$$\nabla F(\mathbf{x}) = \begin{bmatrix} \frac{\partial}{\partial x_1} F(\mathbf{x}) \\ \frac{\partial}{\partial x_2} F(\mathbf{x}) \end{bmatrix} = \begin{bmatrix} 2x_1 + 2x_2 + 1 \\ 2x_1 + 4x_2 \end{bmatrix} \qquad \mathbf{g}_0 = \nabla F(\mathbf{x})\Big|_{\mathbf{x} = \mathbf{x}_0} = \begin{bmatrix} 3 \\ 3 \end{bmatrix}$$

$$\mathbf{x}_1 = \mathbf{x}_0 - \alpha \mathbf{g}_0 = \begin{bmatrix} 0.5 \\ 0.5 \end{bmatrix} - 0.1 \begin{bmatrix} 3 \\ 3 \end{bmatrix} = \begin{bmatrix} 0.2 \\ 0.2 \end{bmatrix}$$

$$\mathbf{x}_2 = \mathbf{x}_1 - \alpha \mathbf{g}_1 = \begin{bmatrix} 0.2 \\ 0.2 \end{bmatrix} - 0.1 \begin{bmatrix} 1.8 \\ 1.2 \end{bmatrix} = \begin{bmatrix} 0.02 \\ 0.08 \end{bmatrix}$$

Plot



Newton’s method

$$F(\mathbf{x}_{k+1}) = F(\mathbf{x}_k + \Delta\mathbf{x}_k) \approx F(\mathbf{x}_k) + \mathbf{g}_k^T \Delta\mathbf{x}_k + \frac{1}{2}\Delta\mathbf{x}_k^T \mathbf{A}_k \Delta\mathbf{x}_k$$

Take the gradient of this second-order approximation and set it equal to zero to find the stationary point:

$$\mathbf{g}_k + \mathbf{A}_k \Delta\mathbf{x}_k = \mathbf{0}$$

$$\Delta\mathbf{x}_k = -\mathbf{A}_k^{-1}\mathbf{g}_k$$

$$\boxed{\mathbf{x}_{k+1} = \mathbf{x}_k - \mathbf{A}_k^{-1}\mathbf{g}_k}$$

Example

$$F(\mathbf{x}) = x_1^2 + 2x_1x_2 + 2x_2^2 + x_1$$

$$\mathbf{x}_0 = \begin{bmatrix} 0.5 \\ 0.5 \end{bmatrix}$$

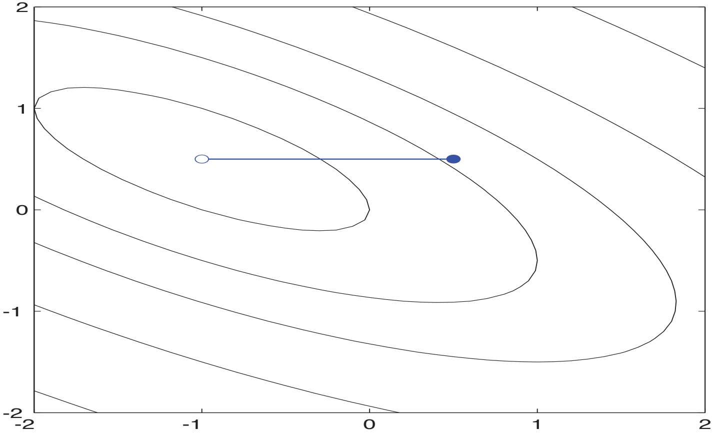
$$\nabla F(\mathbf{x}) = \begin{bmatrix} \frac{\partial}{\partial x_1} F(\mathbf{x}) \\ \frac{\partial}{\partial x_2} F(\mathbf{x}) \end{bmatrix} = \begin{bmatrix} 2x_1 + 2x_2 + 1 \\ 2x_1 + 4x_2 \end{bmatrix}$$

$$\mathbf{g}_0 = \nabla F(\mathbf{x})\Big|_{\mathbf{x} = \mathbf{x}_0} = \begin{bmatrix} 3 \\ 3 \end{bmatrix}$$

$$\mathbf{A} = \begin{bmatrix} 2 & 2 \\ 2 & 4 \end{bmatrix}$$

$$\mathbf{x}_1 = \begin{bmatrix} 0.5 \\ 0.5 \end{bmatrix} - \begin{bmatrix} 2 & 2 \\ 2 & 4 \end{bmatrix}^{-1} \begin{bmatrix} 3 \\ 3 \end{bmatrix} = \begin{bmatrix} 0.5 \\ 0.5 \end{bmatrix} - \begin{bmatrix} 1 & -0.5 \\ -0.5 & 0.5 \end{bmatrix} \begin{bmatrix} 3 \\ 3 \end{bmatrix} = \begin{bmatrix} 0.5 \\ 0.5 \end{bmatrix} - \begin{bmatrix} 1.5 \\ 0 \end{bmatrix} = \begin{bmatrix} -1 \\ 0.5 \end{bmatrix}$$

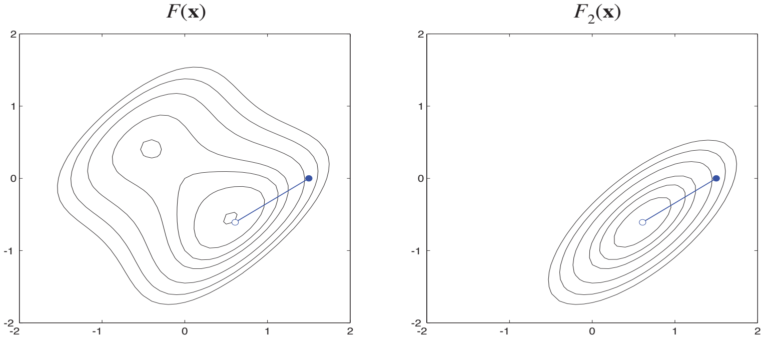
Plot



Non-Quadratic Example

$$F(\mathbf{x}) = (x_2 - x_1)^4 + 8x_1x_2 - x_1 + x_2 + 3$$

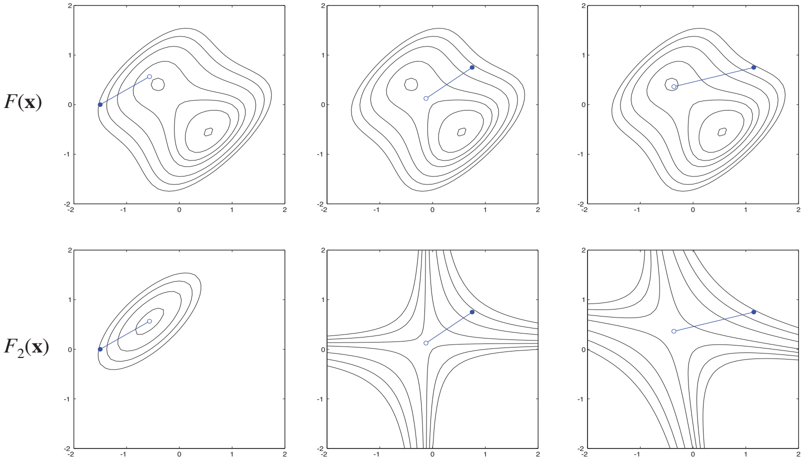
Stationary Points: $\mathbf{x}^1 = \begin{bmatrix} -0.42 \\ 0.42 \end{bmatrix}$ $\mathbf{x}^2 = \begin{bmatrix} -0.13 \\ 0.13 \end{bmatrix}$ $\mathbf{x}^3 = \begin{bmatrix} 0.55 \\ -0.55 \end{bmatrix}$



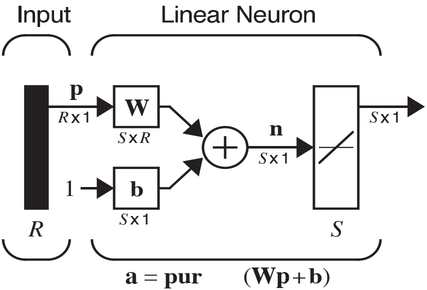
$F(\mathbf{x})$

$F_2(\mathbf{x})$

Different Initial Conditions



ADALINE Network

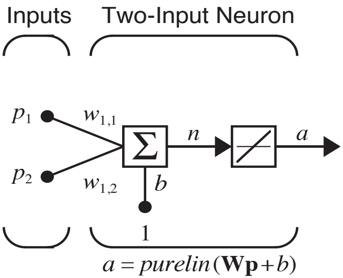


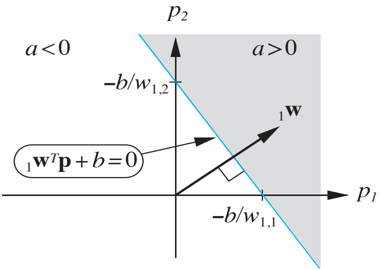
$$\mathbf{a} = \mathbf{purelin}(\mathbf{W}\mathbf{p} + \mathbf{b}) = \mathbf{W}\mathbf{p} + \mathbf{b}$$

$$a_i = purelin(n_i) = purelin({}_i\mathbf{w}^T\mathbf{p} + b_i) = {}_i\mathbf{w}^T\mathbf{p} + b_i$$

$${}_i\mathbf{w} = \begin{bmatrix} w_{i,1} \\ w_{i,2} \\ \vdots \\ w_{i,R} \end{bmatrix}$$

Two input ADALINE





$$a = purelin(n) = purelin({}_1\mathbf{w}^T\mathbf{p} + b) = {}_1\mathbf{w}^T\mathbf{p} + b$$

$$a = {}_1\mathbf{w}^T\mathbf{p} + b = w_{1,1}p_1 + w_{1,2}p_2 + b$$

Mean square error

Training Set:

$$\{\mathbf{p}_1,\mathbf{t}_1\}, \{\mathbf{p}_2,\mathbf{t}_2\}, \ldots, \{\mathbf{p}_Q,\mathbf{t}_Q\}$$

Input: $\mathbf{p}_q$ Target: $\mathbf{t}_q$

Notation:

$$\mathbf{x} = \begin{bmatrix} {}_1\mathbf{w} \\ b \end{bmatrix} \qquad \mathbf{z} = \begin{bmatrix} \mathbf{p} \\ 1 \end{bmatrix} \qquad a = {}_1\mathbf{w}^T\mathbf{p} + b \Rightarrow a = \mathbf{x}^T\mathbf{z}$$

Mean S

$$F(\mathbf{x}) = E[e^2] = E[(t-a)^2] = E[(t-\mathbf{x}^T\mathbf{z})^2]$$

Error analysis

$$F(\mathbf{x}) = E[e^2] = E[(t-a)^2] = E[(t-\mathbf{x}^T\mathbf{z})^2]$$

$$F(\mathbf{x}) = E[t^2 - 2t\mathbf{x}^T\mathbf{z} + \mathbf{x}^T\mathbf{z}\mathbf{z}^T\mathbf{x}]$$

$$F(\mathbf{x}) = E[t^2] - 2\mathbf{x}^T\mathrm{E}[t\mathbf{z}] + \mathbf{x}^T E[\mathbf{z}\mathbf{z}^T]\mathbf{x}$$

$$\boxed{F(\mathbf{x}) = c - 2\mathbf{x}^T\mathbf{h} + \mathbf{x}^T\mathbf{R}\mathbf{x}}$$

$$c = E[t^2] \qquad \mathbf{h} = E[t\mathbf{z}] \qquad \mathbf{R} = E[\mathbf{z}\mathbf{z}^T]$$

The mean square error for the ADALINE Network is a quadratic function:

$$F(\mathbf{x}) = c + \mathbf{d}^T\mathbf{x} + \frac{1}{2}\mathbf{x}^T\mathbf{A}\mathbf{x}$$

$$\mathbf{d} = -2\mathbf{h} \qquad \mathbf{A} = 2\mathbf{R}$$

Approximate Steepest Descent

Approximate mean s

$$\hat{F}(\mathbf{x}) = (t(k) - a(k))^2 = e^2(k)$$

Approximate (stochastic) gradient:

$$\hat{\nabla} F(\mathbf{x}) = \nabla e^2(k)$$

$$[\nabla e^2(k)]_j = \frac{\partial e^2(k)}{\partial w_{1,j}} = 2e(k)\frac{\partial e(k)}{\partial w_{1,j}} \qquad j = 1, 2, \ldots, R$$

$$[\nabla e^2(k)]_{R+1} = \frac{\partial e^2(k)}{\partial b} = 2e(k)\frac{\partial e(k)}{\partial b}$$

Approximate Gradient Calculation

$$\frac{\partial e(k)}{\partial w_{1,j}} = \frac{\partial[t(k) - a(k)]}{\partial w_{1,j}} = \frac{\partial}{\partial \mathrm{w}_{1,j}}[t(k) - ({}_1\mathbf{w}^T\mathbf{p}(k) + b)]$$

$$\frac{\partial e(k)}{\partial w_{1,j}} = \frac{\partial}{\partial w_{1,j}}\left[t(k) - \left(\sum_{i=1}^{R} w_{1,i}p_i(k) + b\right)\right]$$

$$\frac{\partial e(k)}{\partial w_{1,j}} = -p_j(k) \qquad \frac{\partial e(k)}{\partial b} = -1$$

$$\hat{\nabla} F(\mathbf{x}) = \nabla e^2(k) = -2e(k)\mathbf{z}(k)$$

LMS Algorithm

$$\mathbf{x}_{k+1} = \mathbf{x}_k - \alpha \nabla F(\mathbf{x}) \Big|_{\mathbf{x} = \mathbf{x}_k}$$

$$\mathbf{x}_{k+1} = \mathbf{x}_k + 2\alpha e(k) \mathbf{z}(k)$$

$${}_1\mathbf{w}(k+1) = {}_1\mathbf{w}(k) + 2\alpha e(k) \mathbf{p}(k)$$

$$b(k+1) = b(k) + 2\alpha e(k)$$

Multiple-Neuron Case

$${}_{i}\mathbf{w}(k+1) = {}_{i}\mathbf{w}(k) + 2\alpha e_i(k)\mathbf{p}(k)$$

$$b_i(k+1) = b_i(k) + 2\alpha e_i(k)$$

Matrix Form:

$$\boxed{\begin{aligned} \mathbf{W}(k+1) &= \mathbf{W}(k) + 2\alpha\mathbf{e}(k)\mathbf{p}^T(k) \\ \mathbf{b}(k+1) &= \mathbf{b}(k) + 2\alpha\mathbf{e}(k) \end{aligned}}$$

Example

Banana $\left\{\mathbf{p}_1 = \begin{bmatrix}-1\\1\\-1\end{bmatrix}, \mathbf{t}_1 = \begin{bmatrix}-1\end{bmatrix}\right\}$ Apple $\left\{\mathbf{p}_2 = \begin{bmatrix}1\\1\\-1\end{bmatrix}, \mathbf{t}_2 = \begin{bmatrix}1\end{bmatrix}\right\}$

$$\mathbf{R} = E[\mathbf{p}\mathbf{p}^T] = \frac{1}{2}\mathbf{p}_1\mathbf{p}_1^T + \frac{1}{2}\mathbf{p}_2\mathbf{p}_2^T$$

$$\mathbf{R} = \frac{1}{2}\begin{bmatrix}-1\\1\\-1\end{bmatrix}\begin{bmatrix}-1 & 1 & -1\end{bmatrix} + \frac{1}{2}\begin{bmatrix}1\\1\\-1\end{bmatrix}\begin{bmatrix}1 & 1 & -1\end{bmatrix} = \begin{bmatrix}1 & 0 & 0\\0 & 1 & -1\\0 & -1 & 1\end{bmatrix}$$

$$\lambda_1 = 1.0, \qquad \lambda_2 = 0.0, \qquad \lambda_3 = 2.0$$

$$\alpha < \frac{1}{\lambda_{max}} = \frac{1}{2.0} = 0.5$$

Iteration One

Banana $$a(0) = \mathbf{W}(0)\mathbf{p}(0) = \mathbf{W}(0)\mathbf{p}_1 = \begin{bmatrix} 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} -1 \\ 1 \\ -1 \end{bmatrix} = 0$$

$$e(0) = t(0) - a(0) = t_1 - a(0) = -1 - 0 = -1$$

$$\mathbf{W}(1) = \mathbf{W}(0) + 2\alpha e(0)\mathbf{p}^T(0)$$

$$\mathbf{W}(1) = \begin{bmatrix} 0 & 0 & 0 \end{bmatrix} + 2(0.2)(-1) \begin{bmatrix} -1 \\ 1 \\ -1 \end{bmatrix}^T = \begin{bmatrix} 0.4 & -0.4 & 0.4 \end{bmatrix}$$

Iteration Two

Apple $$a(1) = \mathbf{W}(1)\mathbf{p}(1) = \mathbf{W}(1)\mathbf{p}_2 = \begin{bmatrix} 0.4 & -0.4 & 0.4 \end{bmatrix} \begin{bmatrix} 1 \\ 1 \\ -1 \end{bmatrix} = -0.4$$

$$e(1) = t(1) - a(1) = t_2 - a(1) = 1 - (-0.4) = 1.4$$

$$\mathbf{W}(2) = \begin{bmatrix} 0.4 & -0.4 & 0.4 \end{bmatrix} + 2(0.2)(1.4) \begin{bmatrix} 1 \\ 1 \\ -1 \end{bmatrix}^T = \begin{bmatrix} 0.96 & 0.16 & -0.16 \end{bmatrix}$$

Iteration three

$$a(2) = \mathbf{W}(2)\mathbf{p}(2) = \mathbf{W}(2)\mathbf{p}_1 = \begin{bmatrix} 0.96 & 0.16 & -0.16 \end{bmatrix} \begin{bmatrix} -1 \\ 1 \\ -1 \end{bmatrix} = -0.64$$

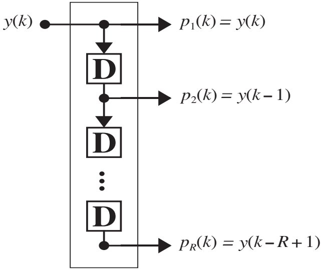
$$e(2) = t(2) - a(2) = t_1 - a(2) = -1 - (-0.64) = -0.36$$

$$\mathbf{W}(3) = \mathbf{W}(2) + 2\alpha e(2)\mathbf{p}^T(2) = \begin{bmatrix} 1.1040 & 0.0160 & -0.0160 \end{bmatrix}$$

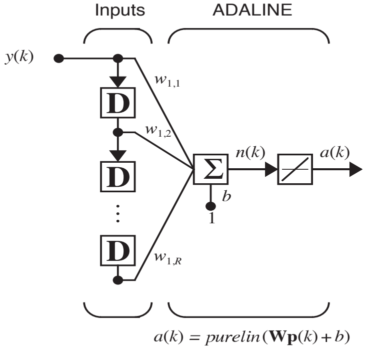
$$\mathbf{W}(\infty) = \begin{bmatrix} 1 & 0 & 0 \end{bmatrix}$$

Adaptive Filtering

Tapped Delay Line

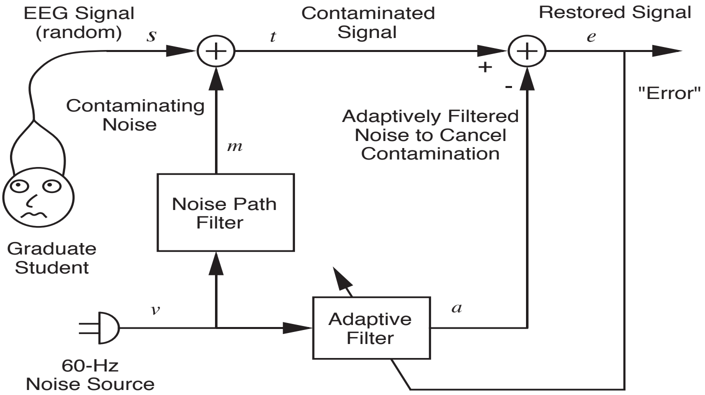


Adaptive Filter



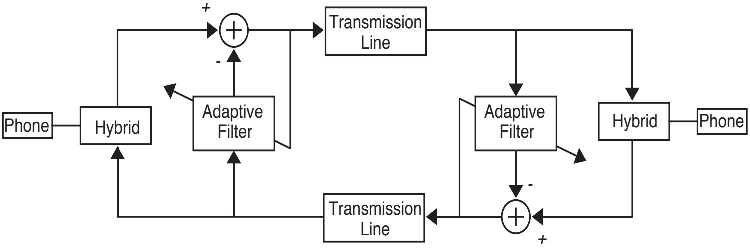
$$a(k) = purelin(\mathbf{Wp} + b) = \sum_{i=1}^{R} w_{1,\,i}\,y(k - i + 1) + b$$

Example: Noise Cancellation



Adaptive Filter Adjusts to Minimize Error (and in doing this removes 60-Hz noise from contaminated signal)

Echo Cancellation



Next lecture

- Multi layer network will be discussed.
- Training and testing of feedforward network will be discussed.
- Overfitting, extrapolation and regularization will be discussed.
- Read ahead the Chapter 11 and 13 from the Neural Network Design book.