Deep Generative Models

Supervised vs Unsupervised Learning

Supervised Learning

Data: (x, y)
x is data, y is label

Goal: Learn a *function* to map x -> y

Examples: Classification, regression, object detection, semantic segmentation, image captioning, etc.

Supervised vs Unsupervised Learning

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Cat

Classification

Supervised vs Unsupervised Learning

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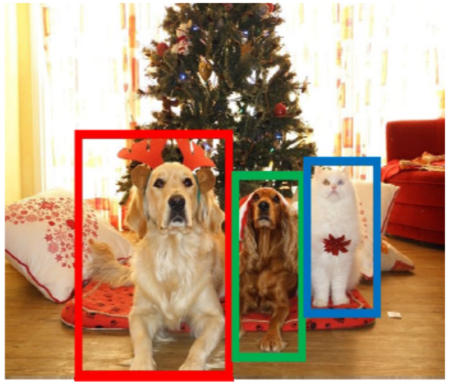

DOG, DOG, CAT

Object Detection

Supervised vs Unsupervised Learning

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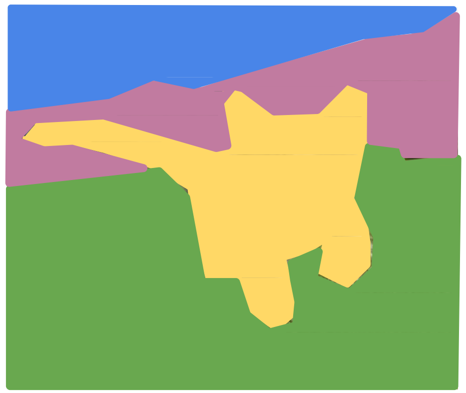

GRASS, CAT, TREE, SKY

Semantic Segmentation

Supervised vs Unsupervised Learning

Supervised Learning

Data: (x, y)
x is data, y is label

Goal: Learn a *function* to map x -> y

Examples: Classification, regression, object detection, semantic segmentation, image captioning, etc.

A cat sitting on a suitcase on the floor

Image captioning

Supervised vs Unsupervised Learning

Unsupervised Learning

Data: x
Just data, no labels!

Goal: Learn some underlying hidden *structure* of the data

Examples: Clustering, dimensionality reduction, feature learning, density estimation, etc.

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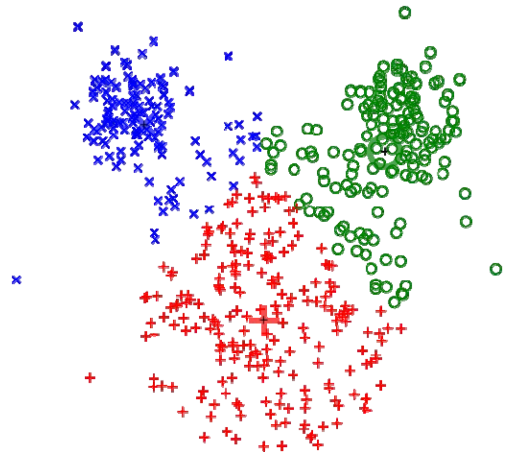

K-means clustering

Supervised vs Unsupervised Learning

Unsupervised Learning

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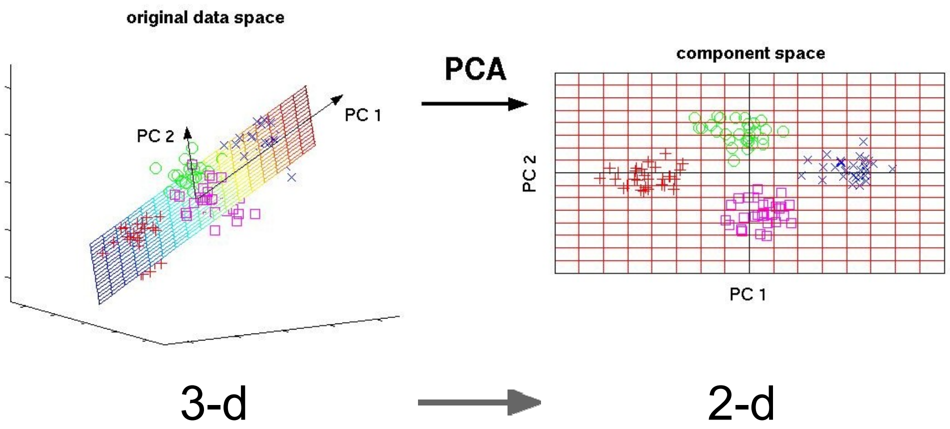
Goal: Learn some underlying hidden *structure* of the data

Examples: Clustering, dimensionality reduction, feature learning, density estimation, etc.



Principal Component Analysis
(Dimensionality reduction)

Supervised vs Unsupervised Learning

Unsupervised Learning

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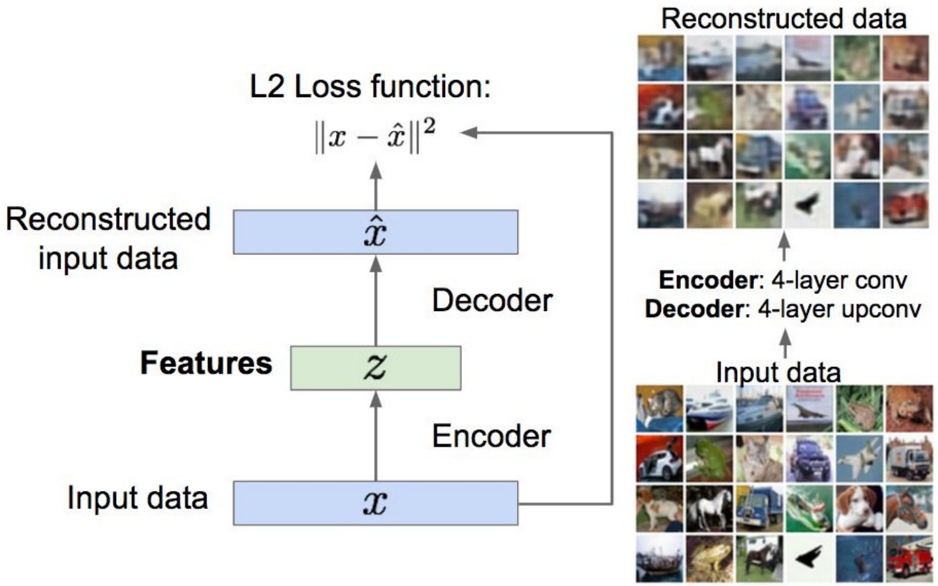
Just data, no labels!

Goal: Learn some underlying hidden *structure* of the data

Examples: Clustering, dimensionality reduction, feature learning, density estimation, etc.



Autoencoders
(Feature learning)

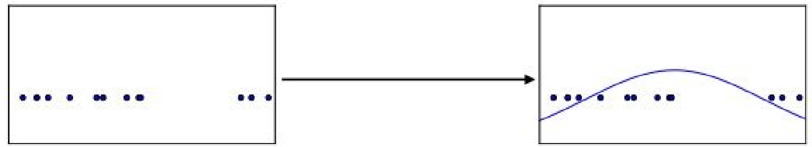
Supervised vs Unsupervised Learning

Unsupervised Learning

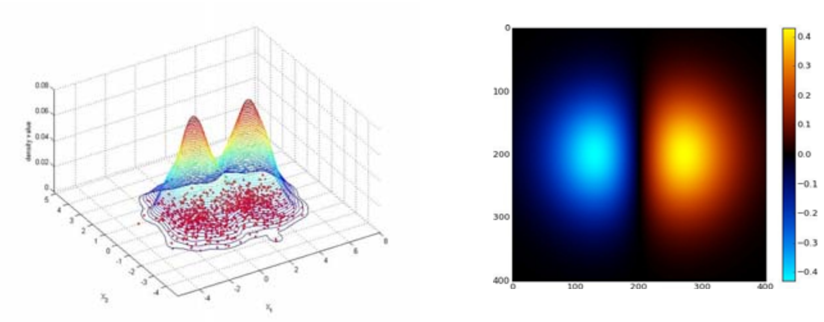
Data: x
Just data, no labels!

Goal: Learn some underlying hidden *structure* of the data

Examples: Clustering, dimensionality reduction, feature learning, density estimation, etc.



1-d density estimation



2-d density estimation

Supervised vs Unsupervised Learning

Supervised Learning

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Goal: Learn a *function* to map x -> y

Examples: Classification, regression, object detection, semantic segmentation, image captioning, etc.

Unsupervised Learning

Data: x
Just data, no labels!

Goal: Learn some underlying hidden *structure* of the data

Examples: Clustering, dimensionality reduction, feature learning, density estimation, etc.

Supervised vs Unsupervised Learning

Supervised Learning

Data: (x, y)
x is data, y is label

Goal: Learn a *function* to map x -> y

Examples: Classification, regression, object detection, semantic segmentation, image captioning, etc.

Unsupervised Learning

Training data is cheap

Data: x
Just data, no labels!

Holy grail: Solve unsupervised learning => understand structure of visual world

Goal: Learn some underlying hidden *structure* of the data

Examples: Clustering, dimensionality reduction, feature learning, density estimation, etc.

Generative Models

Given training data, generate new samples from same distribution

Training data ~ $p_{data}(x)$

Generated samples ~ $p_{model}(x)$

Want to learn $p_{model}(x)$ similar to $p_{data}(x)$

Generative Models

Given training data, generate new samples from same distribution

Training data ~ $p_{data}(x)$

Generated samples ~ $p_{model}(x)$

Want to learn $p_{model}(x)$ similar to $p_{data}(x)$

Addresses density estimation, a core problem in unsupervised learning

Several flavors:

- Explicit density estimation: explicitly define and solve for $p_{model}(x)$
- Implicit density estimation: learn model that can sample from $p_{model}(x)$ w/o explicitly defining it

Why Generative Models?

- Realistic samples for artwork, super-resolution, colorization, etc.

- Generative models of time-series data can be used for simulation and planning (reinforcement learning applications!)
- Training generative models can also enable inference of latent representations that can be useful as general features

Taxonomy of Generative Models

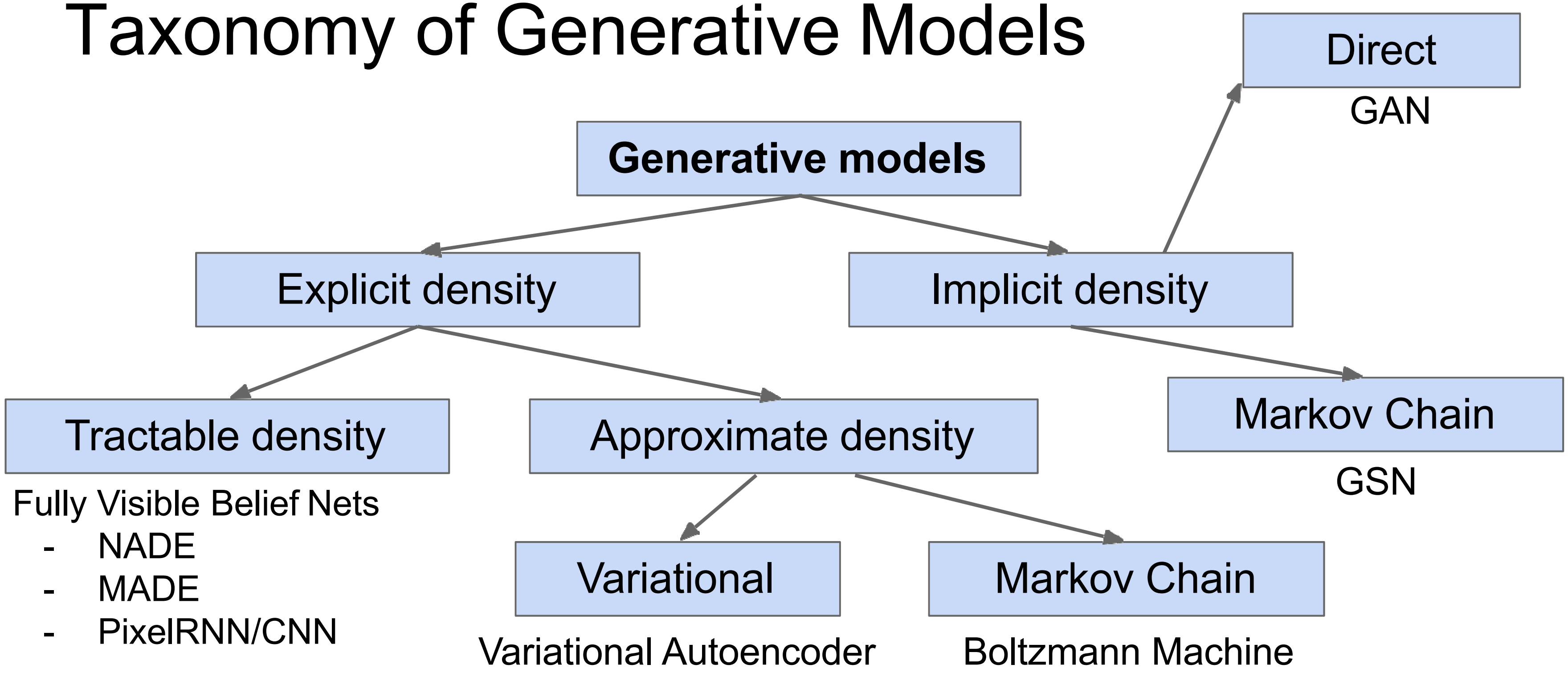
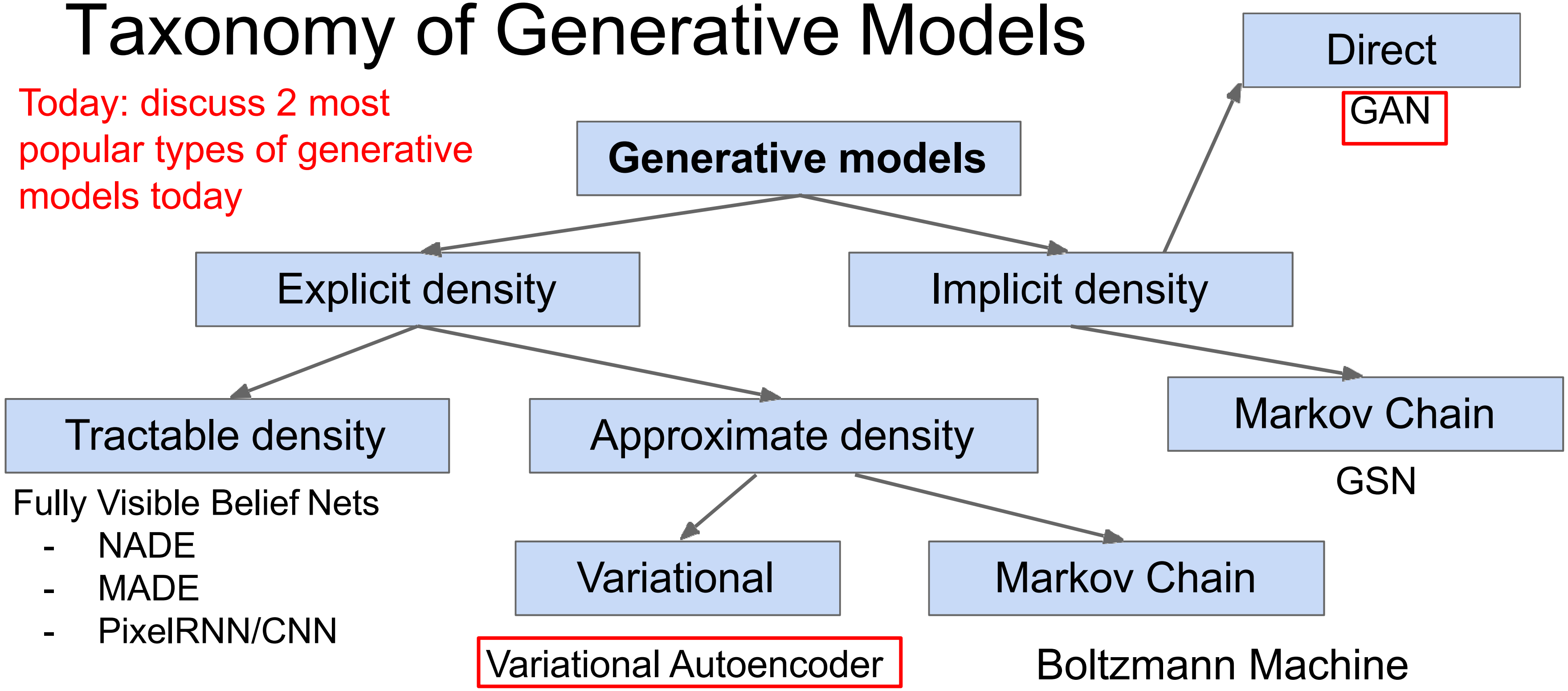


Figure copyright and adapted from Ian Goodfellow, Tutorial on Generative Adversarial Networks, 2017.

Taxonomy of Generative Models

Today: discuss 2 most popular types of generative models today



Variational Autoencoders (VAE)

VAE

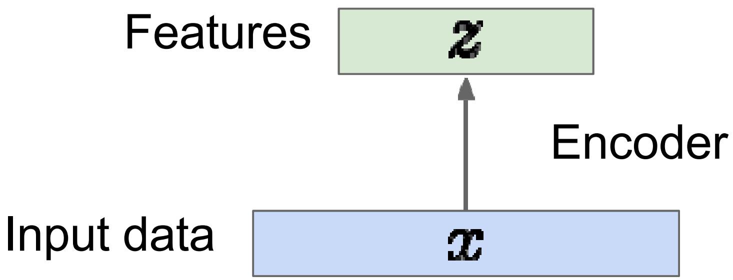
VAEs define intractable density function with latent **z**:

$$p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$$

Cannot optimize directly, derive and optimize lower bound on likelihood instead

Background: Autoencoders

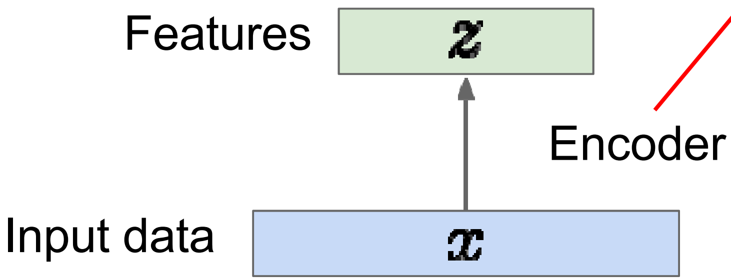
Unsupervised approach for learning a lower-dimensional feature representation from unlabeled training data



Background: Autoencoders

Unsupervised approach for learning a lower-dimensional feature representation from unlabeled training data

Originally: Linear + nonlinearity (sigmoid)
Later: Deep, fully-connected
Later: ReLU CNN



Background: Autoencoders

Unsupervised approach for learning a lower-dimensional feature representation from unlabeled training data

z usually smaller than **x** (dimensionality reduction)

Q: Why dimensionality reduction?

Originally: Linear + nonlinearity (sigmoid)
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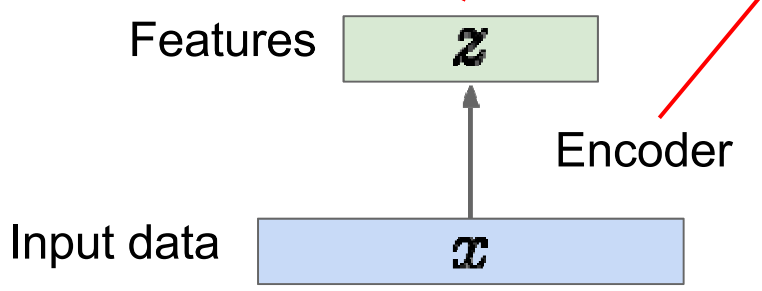


Background: Autoencoders

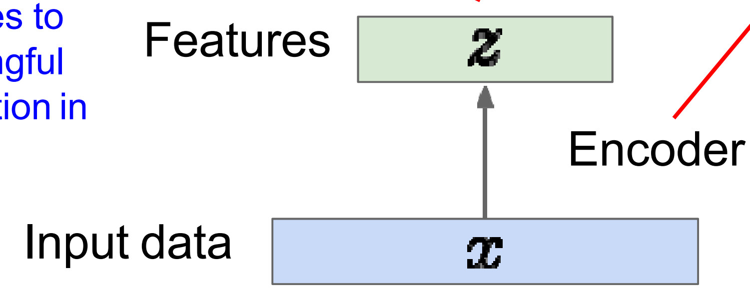
Unsupervised approach for learning a lower-dimensional feature representation from unlabeled training data

z usually smaller than **x** (dimensionality reduction)

Q: Why dimensionality reduction?

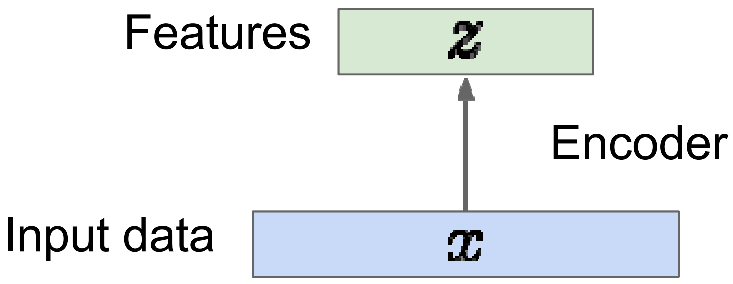
A: Want features to capture meaningful factors of variation in data

Originally: Linear + nonlinearity (sigmoid)
Later: Deep, fully-connected
Later: ReLU CNN



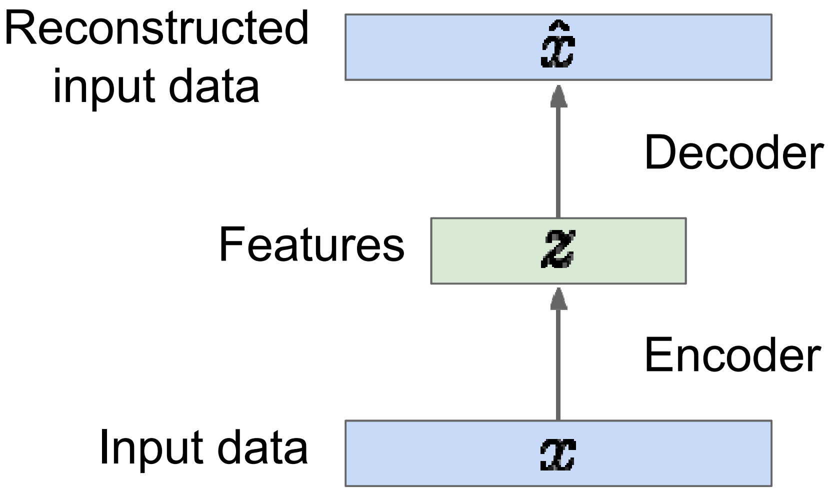
Background: Autoencoders

How to learn this feature representation?



Background: Autoencoders

How to learn this feature representation?
Train such that features can be used to reconstruct original data
“Autoencoding” - encoding itself



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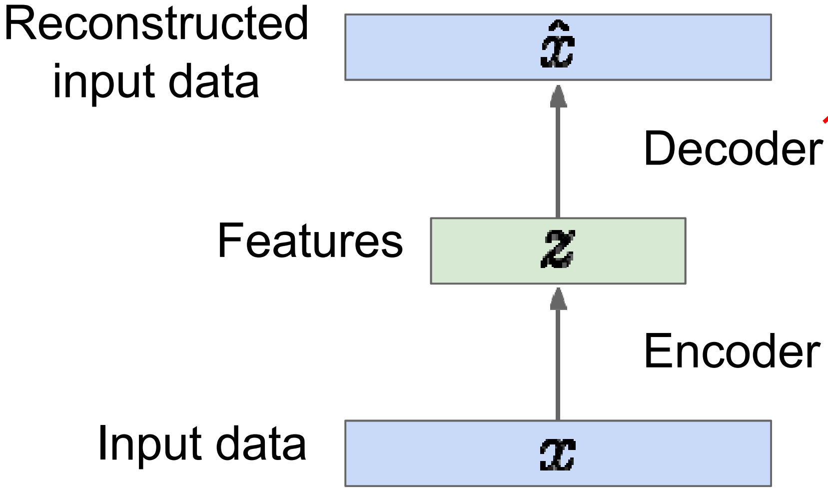

Originally: Linear + nonlinearity (sigmoid)

Later: Deep, fully-connected

Later: ReLU CNN (upconv)

Background: Autoencoders

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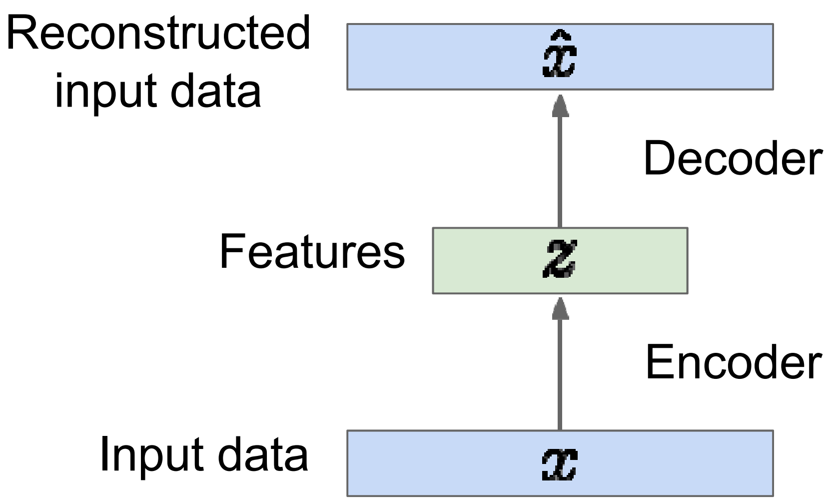
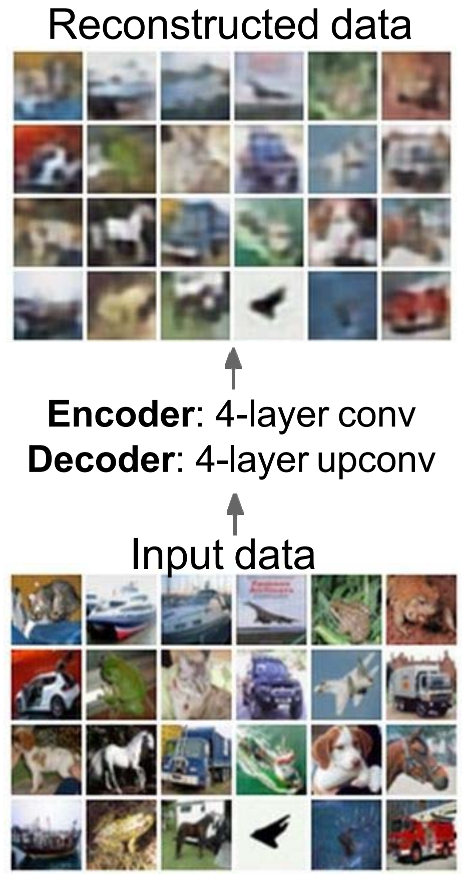
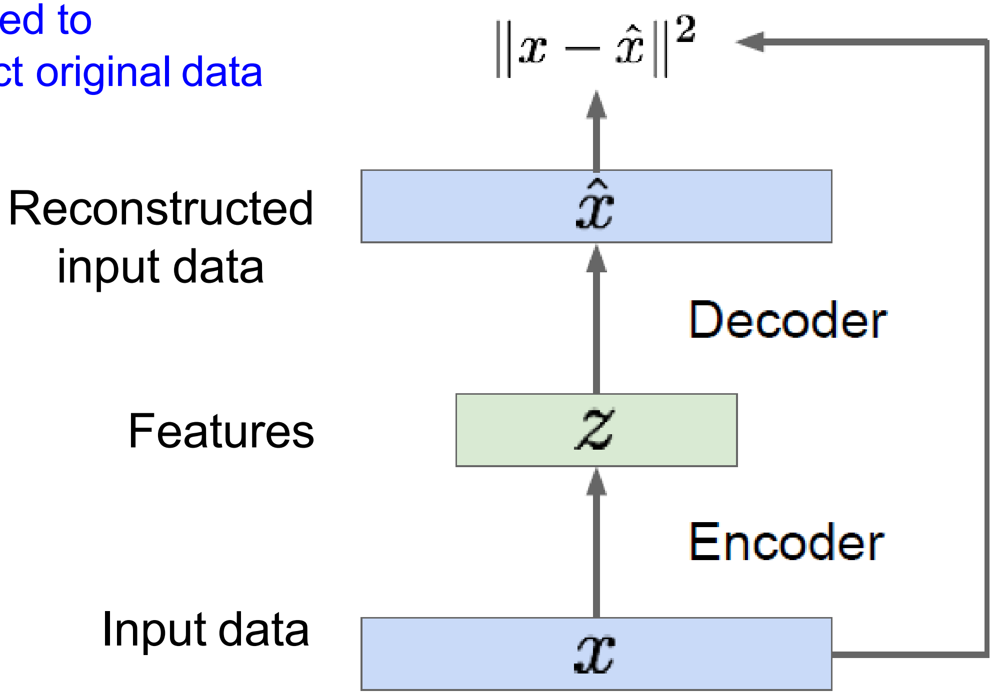


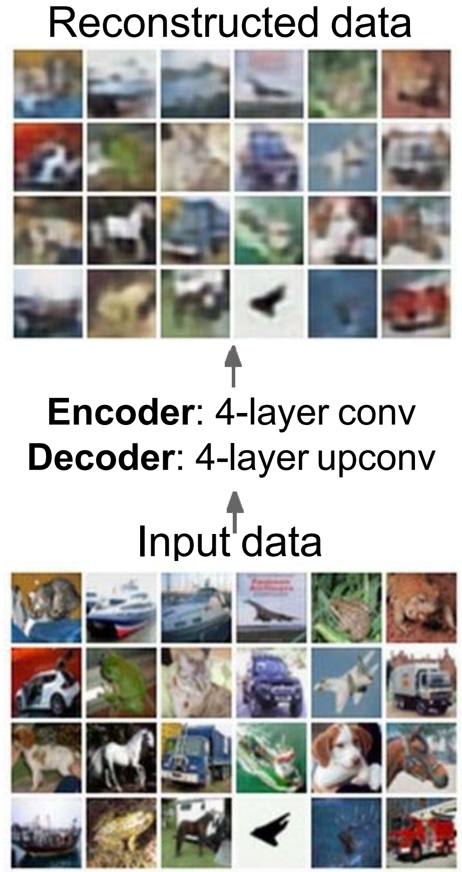


Background: Autoencoders

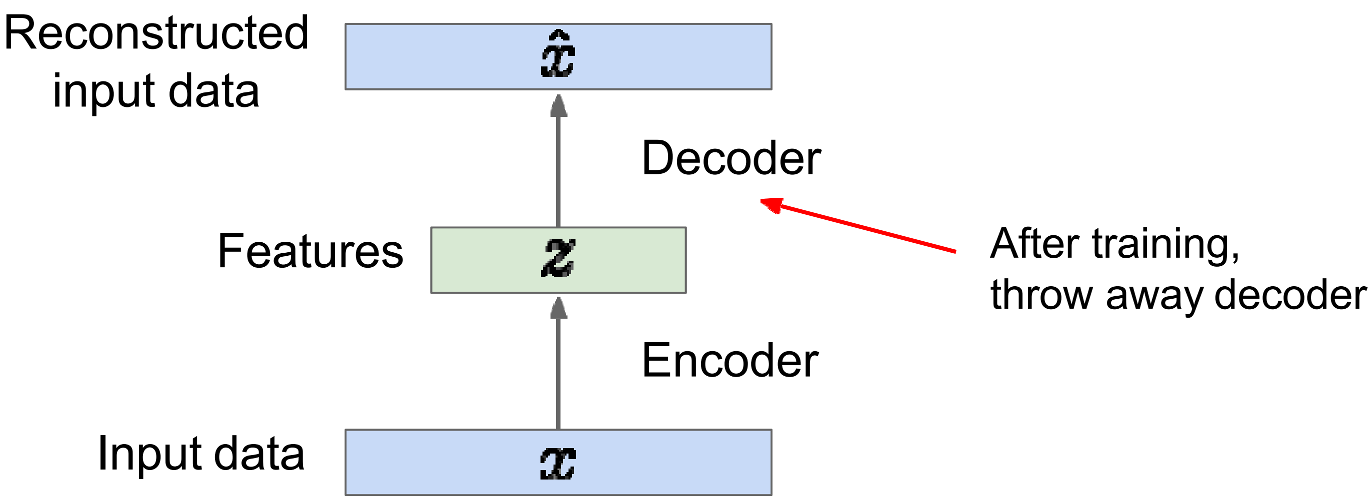
Train such that features can be used to reconstruct original data

L2 Loss function:



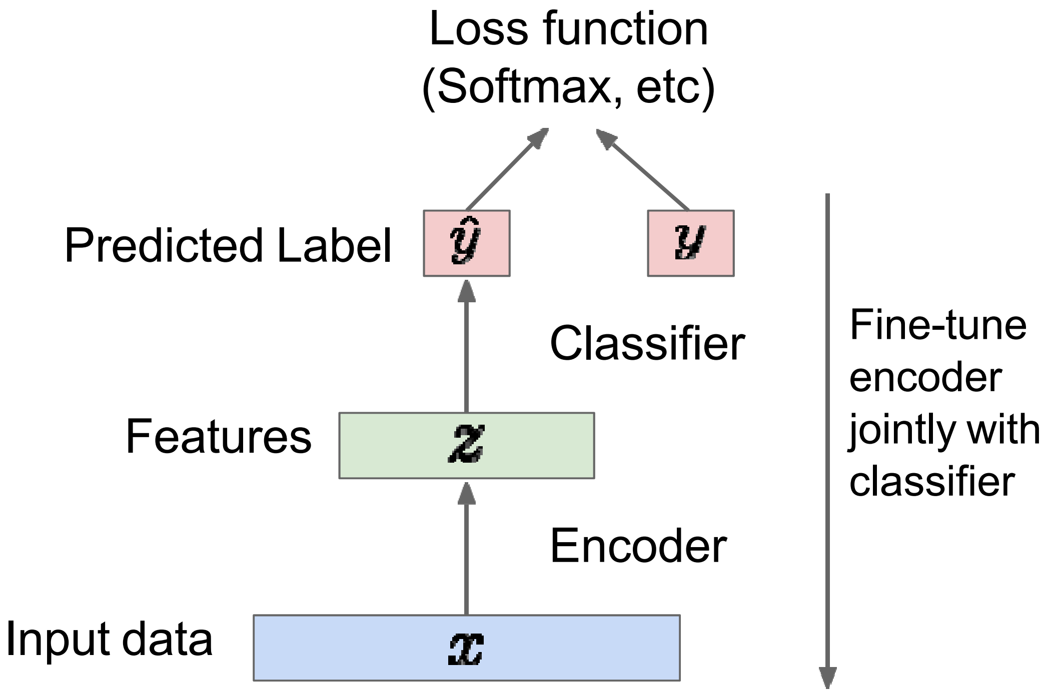


Background: Autoencoders



Background: Autoencoders

Encoder can be used to initialize a **supervised** model

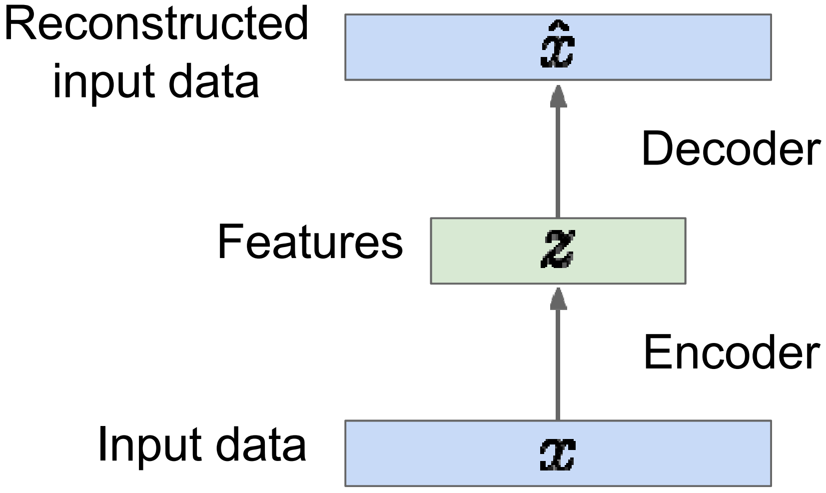


bird plane

dog deer truck

Train for final task (sometimes with small data)

Background: Autoencoders



Autoencoders can reconstruct data, and can learn features to initialize a supervised model

Features capture factors of variation in training data. Can we generate new images from an autoencoder?

Variational Autoencoders

Probabilistic spin on autoencoders - will let us sample from the model to generate data!

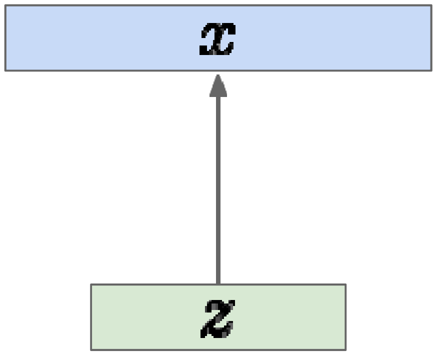
Variational Autoencoders

Probabilistic spin on autoencoders - will let us sample from the model to generate data!

Assume training data $\{x^{(i)}\}_{i=1}^{N}$ is generated from underlying unobserved (latent) representation **z**

Sample from true conditional $p_{\theta^*}(x \mid z^{(i)})$

Sample from true prior $p_{\theta^*}(z)$



Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders

Probabilistic spin on autoencoders - will let us sample from the model to generate data!

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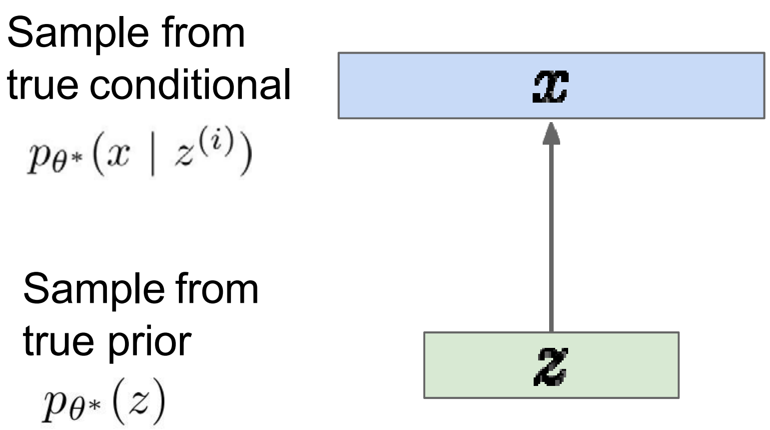


Intuition (remember from autoencoders!): **x** is an image, **z** is latent factors used to generate **x:** attributes, orientation, etc.

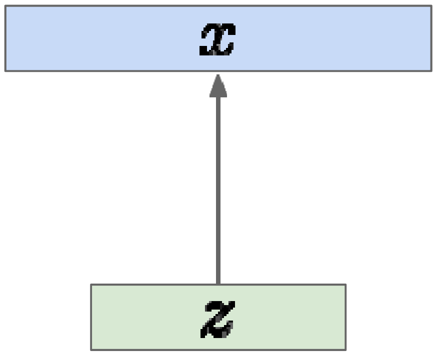
Kingma and Welling, "Auto-Encoding Variational Bayes", ICLR 2014

Variational Autoencoders

We want to estimate the true parameters θ^* of this generative model.

Sample from true conditional

$p_{\theta^*}(x \mid z^{(i)})$



Sample from true prior

$p_{\theta^*}(z)$

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders

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true conditional
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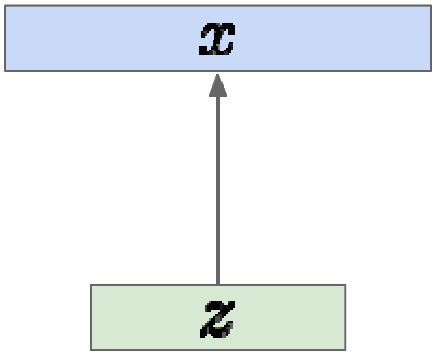

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How should we represent this model?

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Variational Autoencoders

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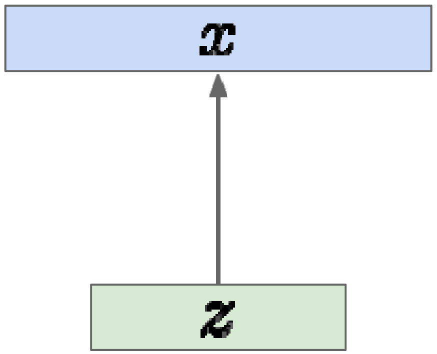


Sample from true prior

$p_{\theta^*}(z)$

We want to estimate the true parameters θ^* of this generative model.

How should we represent this model?

Choose prior p(z) to be simple, e.g. Gaussian. Reasonable for latent attributes, e.g. pose, how much smile.

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

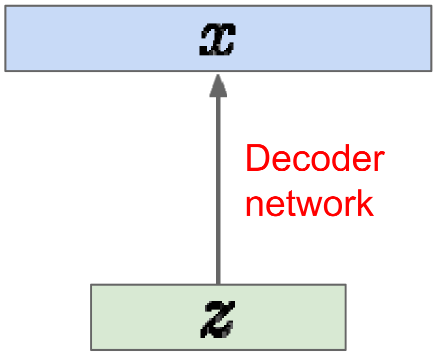
Variational Autoencoders

Sample from true conditional

$p_{\theta^*}(x \mid z^{(i)})$

Sample from true prior

$p_{\theta^*}(z)$



We want to estimate the true parameters θ^* of this generative model.

How should we represent this model?

Choose prior p(z) to be simple, e.g. Gaussian.

Conditional p(x|z) is complex (generates image) => represent with neural network

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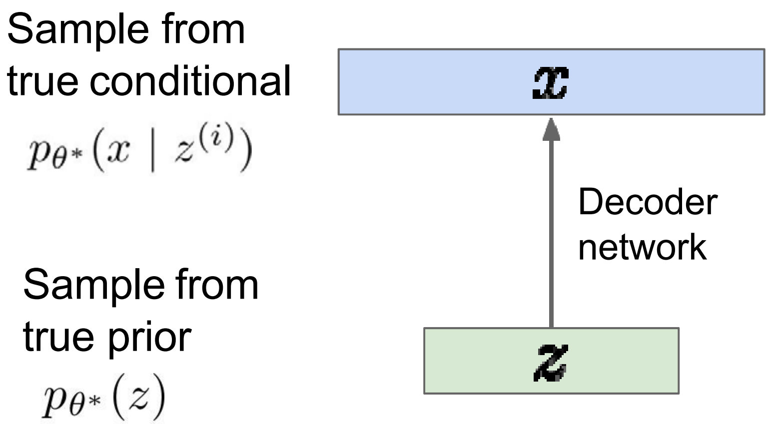
Variational Autoencoders



We want to estimate the true parameters θ^* of this generative model.

How to train the model?

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders

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Sample from
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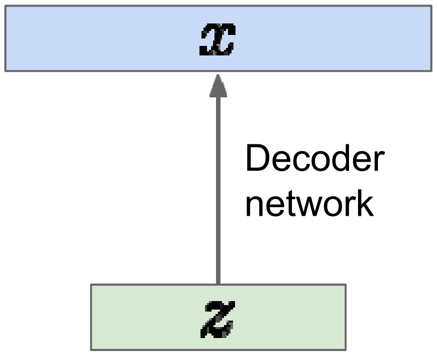

We want to estimate the true parameters θ^*
of this generative model.

How to train the model?

Learn model parameters to maximize
likelihood of training data

$$p_\theta(x) = \int p_\theta(z)p_\theta(x|z)dz$$

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true conditional

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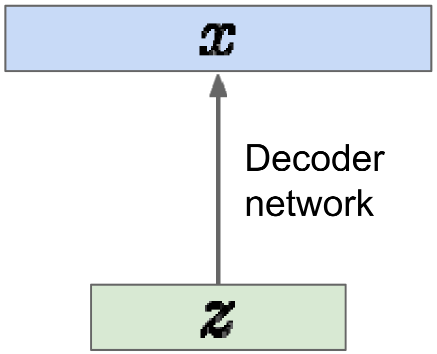

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How to train the model?

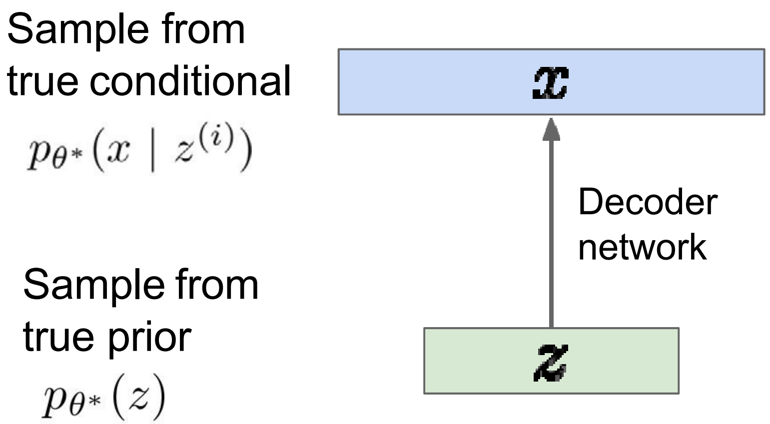
Learn model parameters to maximize likelihood of training data

$$p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$$

Now with latent z

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders



We want to estimate the true parameters θ^* of this generative model.

How to train the model?

Remember strategy for training generative models from FVBNs. Learn model parameters to maximize likelihood of training data

$$p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$$

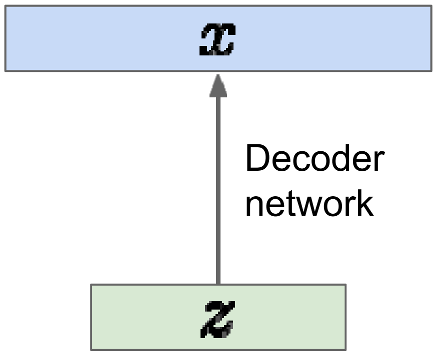
Q: What is the problem with this?

Kingma and Welling, "Auto-Encoding Variational Bayes", ICLR 2014

Variational Autoencoders

Sample from true conditional

$p_{\theta^*}(x \mid z^{(i)})$



Sample from true prior

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How to train the model?

Learn model parameters to maximize likelihood of training data

$$p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$$

Q: What is the problem with this?

Intractable!

Kingma and Welling, "Auto-Encoding Variational Bayes", ICLR 2014

Variational Autoencoders: Intractability

Data likelihood: $p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$

Kingma and Welling, "Auto-Encoding Variational Bayes", ICLR 2014

Variational Autoencoders: Intractability

Data likelihood: $p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$

Simple Gaussian prior

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders: Intractability

Data likelihood: $p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$

Decoder neural network

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders: Intractability

Data likelihood: $p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$

Intractible to compute
p(x|z) for every z!

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders: Intractability

Data likelihood: $p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$

Posterior density also intractable: $p_\theta(z|x) = p_\theta(x|z) p_\theta(z) / p_\theta(x)$

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders: Intractability

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Intractable data likelihood

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders: Intractability

Data likelihood: $p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$

Posterior density also intractable: $p_\theta(z|x) = p_\theta(x|z) p_\theta(z) / p_\theta(x)$

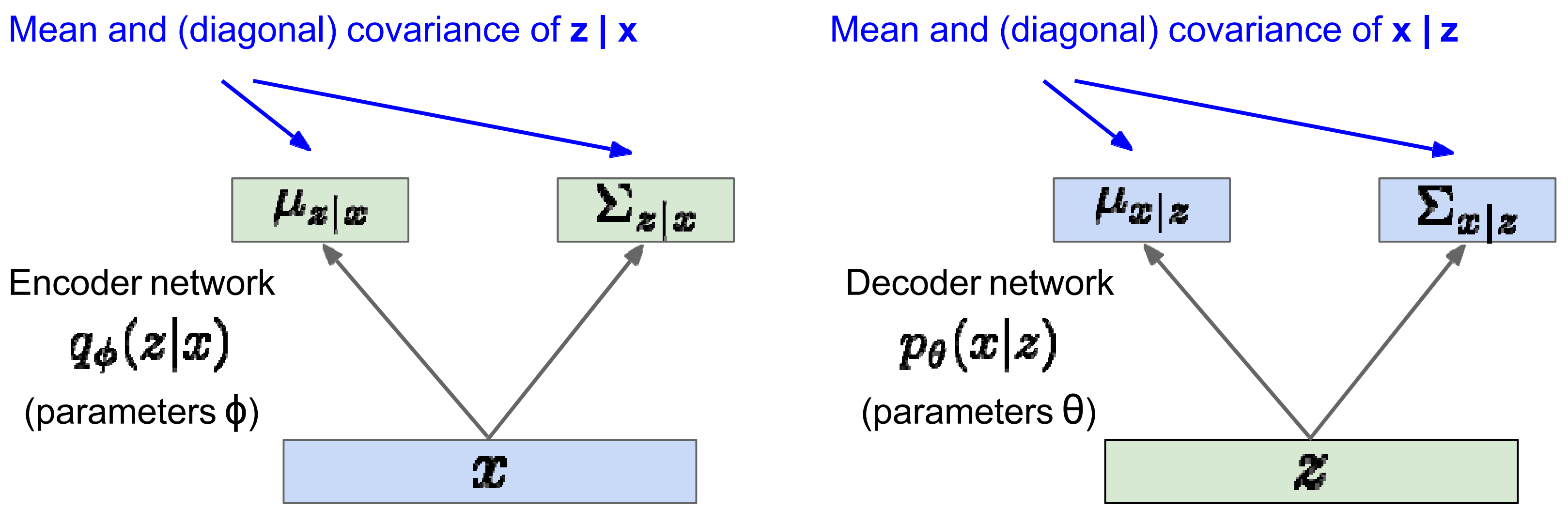
Solution: In addition to decoder network modeling $p_\theta(x|z)$, define additional encoder network $q_\phi(z|x)$ that approximates $p_\theta(z|x)$

Will see that this allows us to derive a lower bound on the data likelihood that is tractable, which we can optimize

Kingma and Welling, "Auto-Encoding Variational Bayes", ICLR 2014

Variational Autoencoders

Since we're modeling probabilistic generation of data, encoder and decoder networks are probabilistic



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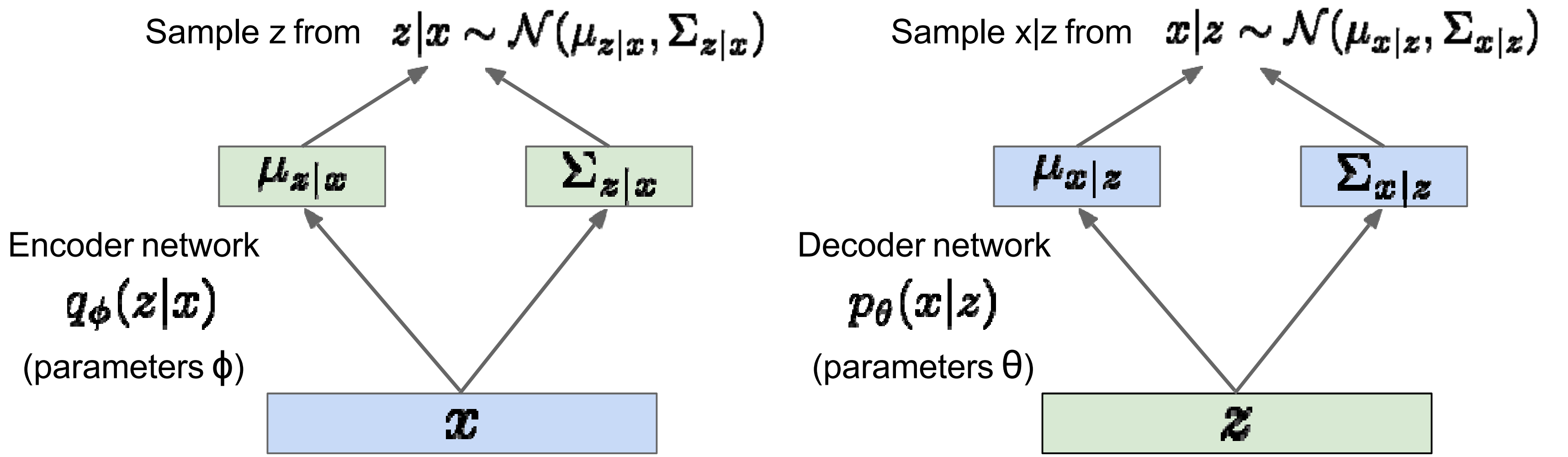

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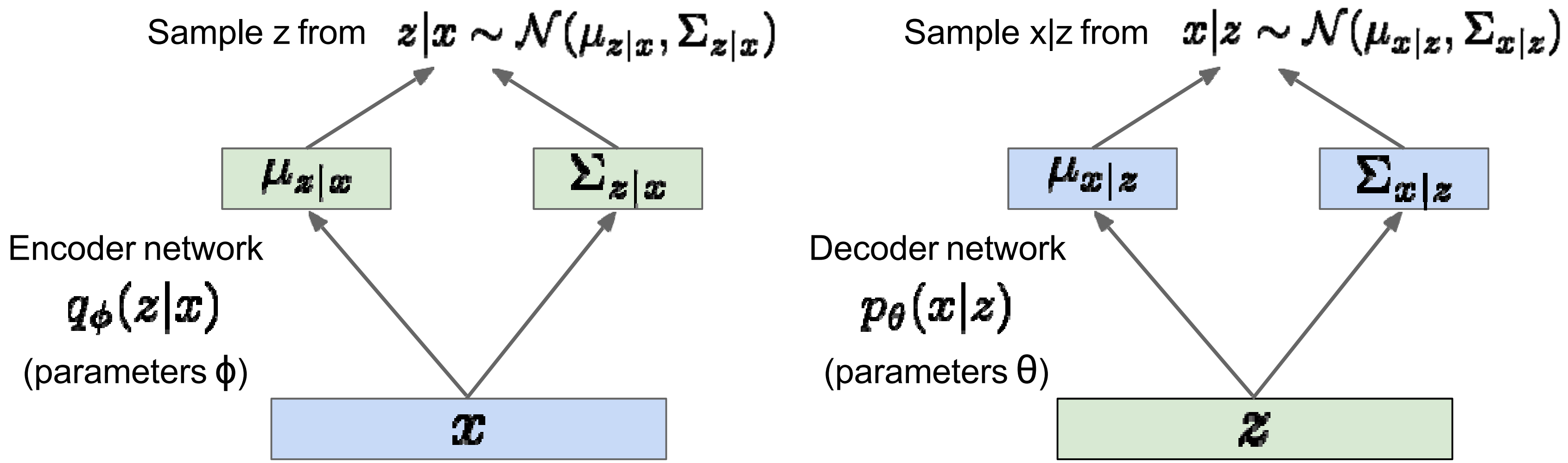

Encoder and decoder networks also called
"recognition"/"inference" and "generation" networks

Kingma and Welling, "Auto-Encoding Variational Bayes", ICLR 2014

Variational Autoencoders

Now equipped with our encoder and decoder networks, let's work out the (log) data likelihood:

$$\log p_\theta(x^{(i)}) = \mathbf{E}_{z \sim q_\phi(z|x^{(i)})} \left[\log p_\theta(x^{(i)}) \right] \quad (p_\theta(x^{(i)}) \text{ Does not depend on } z)$$

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Taking expectation wrt. z
(using encoder network) will
come in handy later

Variational Autoencoders

Now equipped with our encoder and decoder networks, let's work out the (log) data likelihood:

$$\begin{aligned}\log p_\theta(x^{(i)}) &= \mathbf{E}_{z\sim q_\phi(z|x^{(i)})}\left[\log p_\theta(x^{(i)})\right] \quad (p_\theta(x^{(i)}) \text{ Does not depend on } z)\\ &= \mathbf{E}_z\left[\log \frac{p_\theta(x^{(i)} \mid z)p_\theta(z)}{p_\theta(z \mid x^{(i)})}\right] \quad (\text{Bayes' Rule})\end{aligned}$$

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\end{aligned}
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$$= \mathbf{E}_z\left[\log p_\theta(x^{(i)} \mid z)\right] - D_{KL}(q_\phi(z \mid x^{(i)}) \,||\, p_\theta(z)) + D_{KL}(q_\phi(z \mid x^{(i)}) \,||\, p_\theta(z \mid x^{(i)}))$$

The expectation wrt. z (using encoder network) let us write nice KL terms

Variational Autoencoders

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\end{aligned}
$$

Decoder network gives $p_\theta(x|z)$, can compute estimate of this term through sampling. (Sampling differentiable through reparam. trick, see paper.)

This KL term (between Gaussians for encoder and z prior) has nice closed-form solution!

$p_\theta(z|x)$ intractable (saw earlier), can't compute this KL term :(But we know KL divergence always >= 0.

Variational Autoencoders

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\end{aligned}
$$

Tractable lower bound which we can take gradient of and optimize! ($p_\theta(x|z)$ differentiable, KL term differentiable)

Variational Autoencoders

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\end{aligned}
$$

$$\log p_\theta(x^{(i)}) \geq \mathcal{L}(x^{(i)},\theta,\phi)$$

Variational lower bound ("ELBO")

$$\theta^*, \phi^* = \arg\max_{\theta,\phi} \sum_{i=1}^{N} \mathcal{L}(x^{(i)},\theta,\phi)$$

Training: Maximize lower bound

Variational Autoencoders

Now equipped with our encoder and decoder networks, let's work out the (log) data likelihood:

$$\log p_\theta(x^{(i)}) = \mathbf{E}_{z \sim q_\phi(z|x^{(i)})}\left[\log p_\theta(x^{(i)})\right] \quad (p_\theta(x^{(i)}) \text{ Does not depend on } z)$$

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Reconstruct the input data

Make approximate posterior distribution close to prior

$$= \mathbf{E}_z\left[\log p_\theta(x^{(i)} \mid z)\right] - \mathbf{E}_z\left[\log \frac{q_\phi(z \mid x^{(i)})}{p_\theta(z)}\right] + \mathbf{E}_z\left[\log \frac{q_\phi(z \mid x^{(i)})}{p_\theta(z \mid x^{(i)})}\right] \quad \text{(Logarithms)}$$

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Training: Maximize lower bound

Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

$$\underbrace{\mathbf{E}_z \left[\log p_\theta(x^{(i)} \mid z) \right] - D_{KL}(q_\phi(z \mid x^{(i)}) \,||\, p_\theta(z))}_{\mathcal{L}(x^{(i)}, \theta, \phi)}$$

Variational Autoencoders

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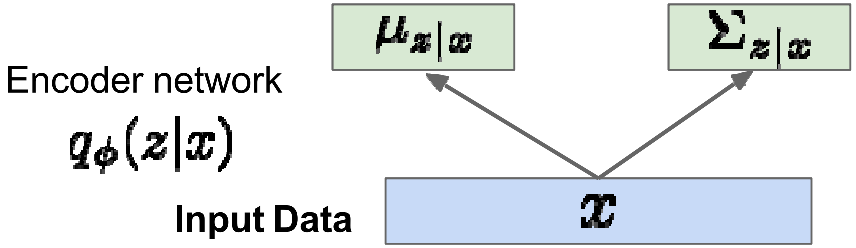
Let’s look at computing the bound (forward pass) for a given minibatch of input data

Input Data x

Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

$$\underbrace{\mathbf{E}_z\left[\log p_\theta(x^{(i)} \mid z)\right] - D_{KL}(q_\phi(z \mid x^{(i)}) \,||\, p_\theta(z))}_{\mathcal{L}(x^{(i)}, \theta, \phi)}$$



Variational Autoencoders

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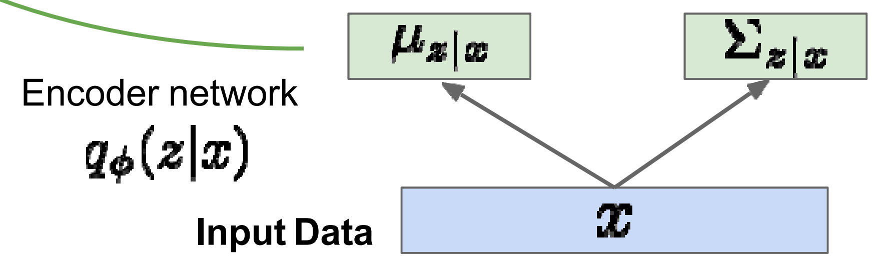

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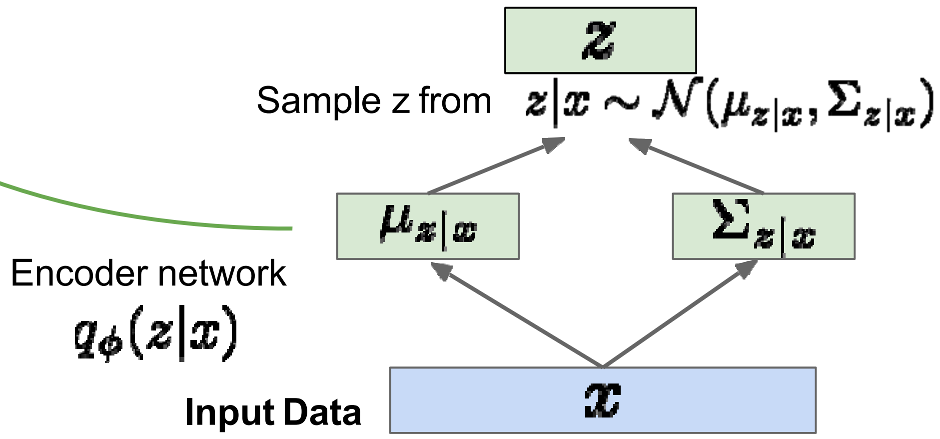

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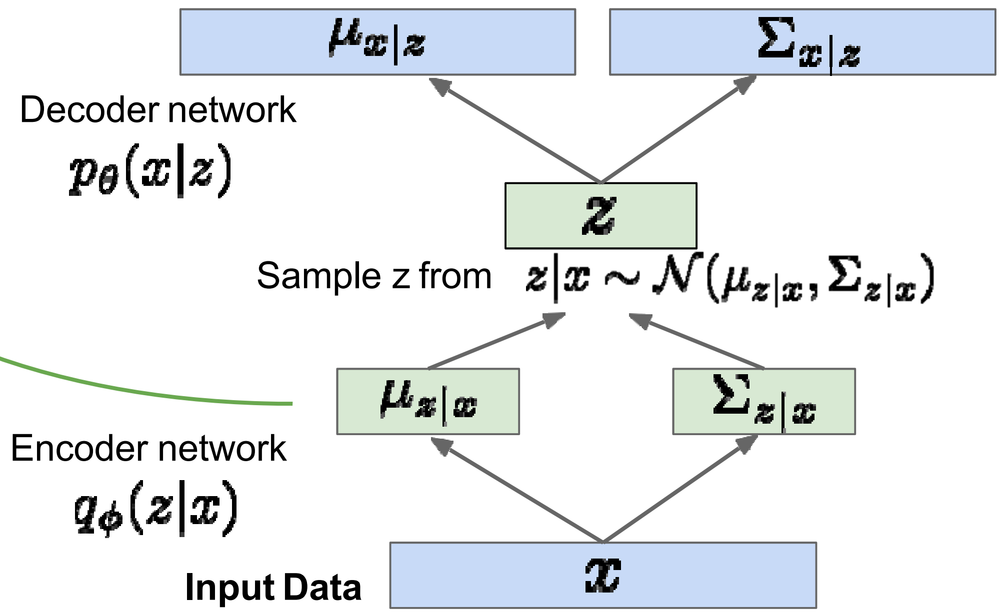

Variational Autoencoders

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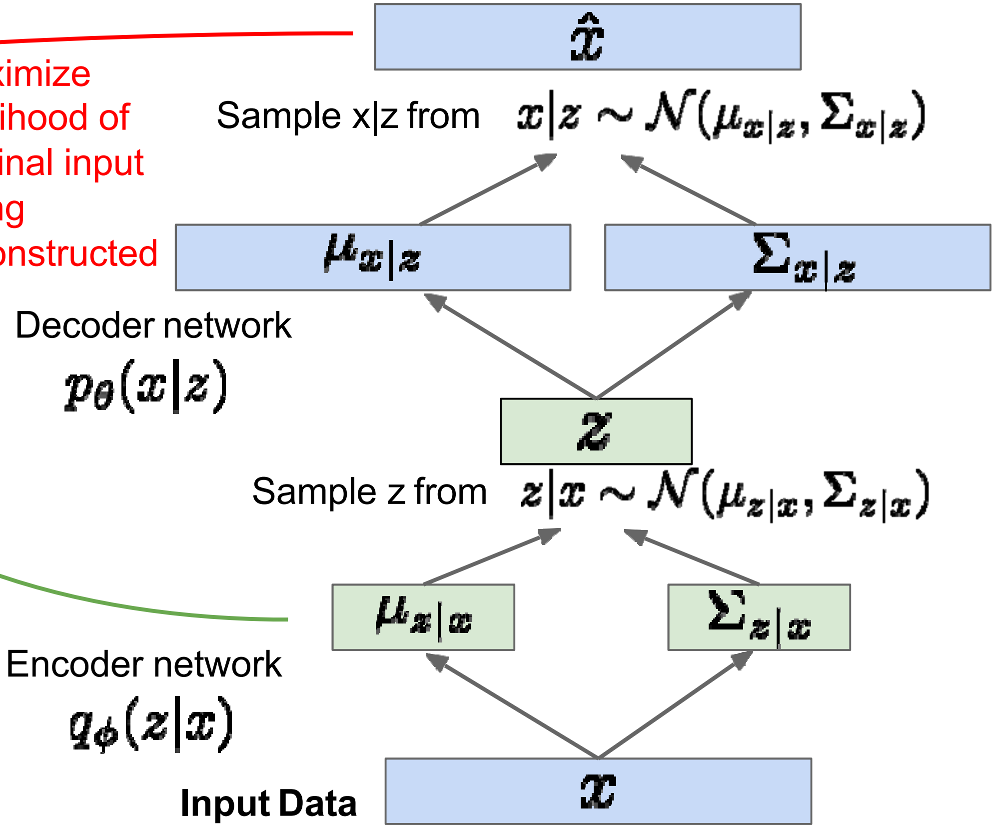
Maximize likelihood of original input being reconstructed

Make approximate posterior distribution close to prior



Variational Autoencoders

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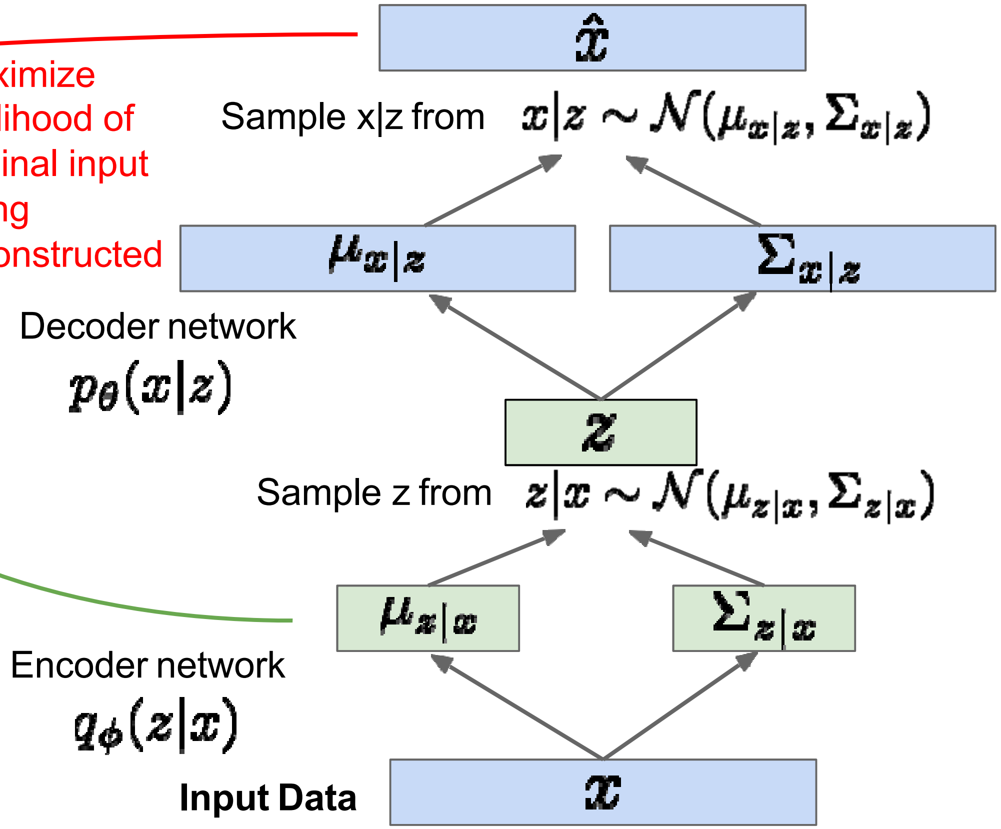
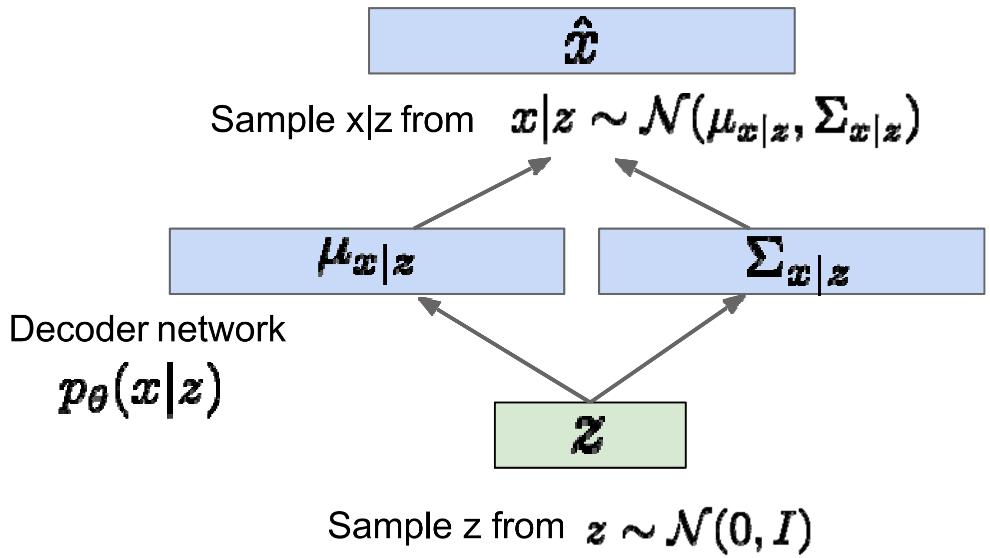


For every minibatch of input data: compute this forward pass, and then backprop!

Variational Autoencoders: Generating Data!

Use decoder network. Now sample z from prior!



Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

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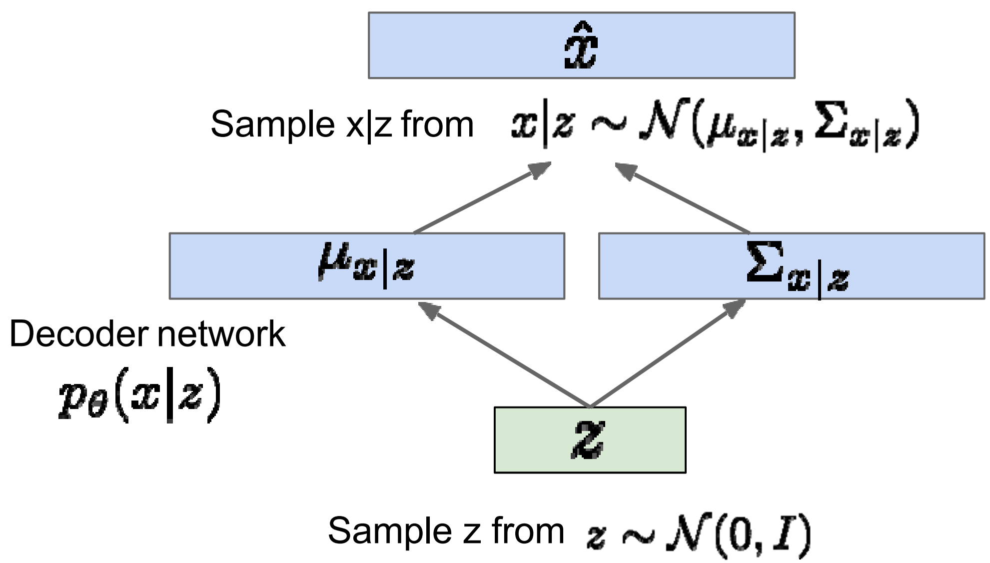

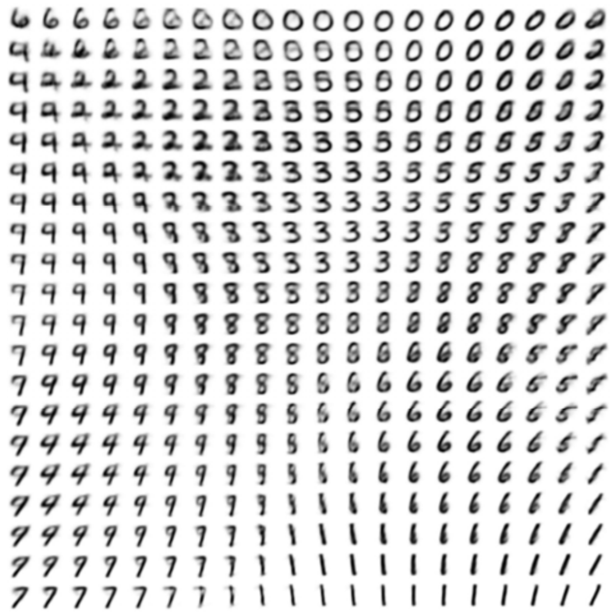

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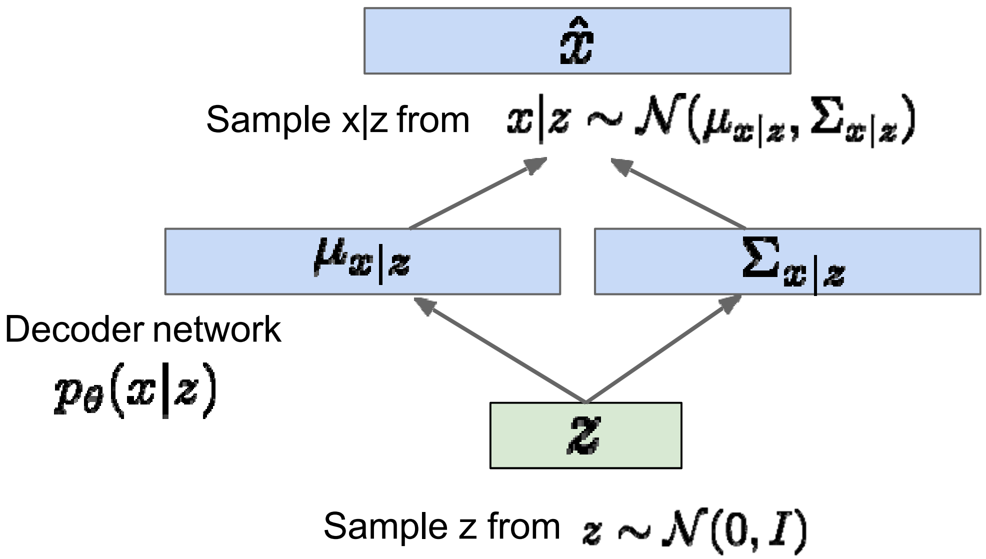

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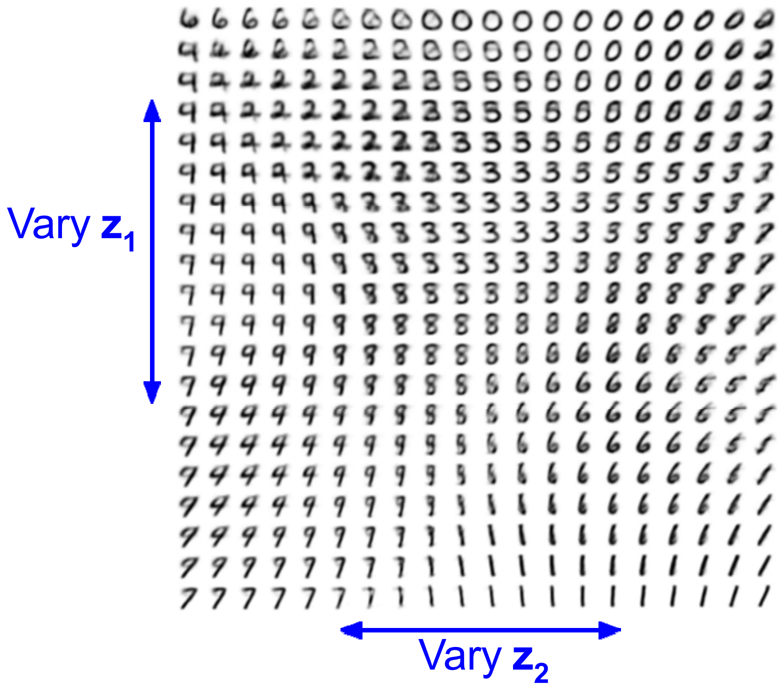
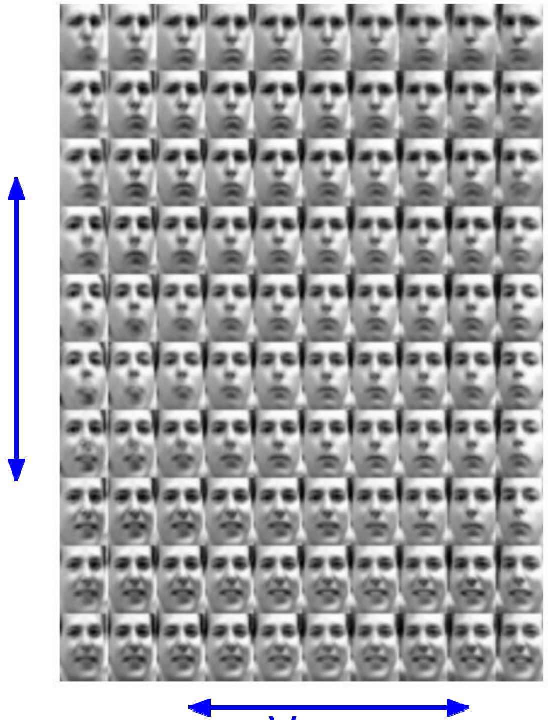
Data manifold for 2-d **z**



Variational Autoencoders: Generating Data!

Diagonal prior on **z** => independent latent variables

Different dimensions of **z** encode interpretable factors of variation



Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders: Generating Data!

Diagonal prior on **z** => independent latent variables

Different dimensions of **z** encode interpretable factors of variation

Also good feature representation that can be computed using $q_\phi(z|x)$!

Degree of smile

Vary $\mathbf{z}_1$

Vary $\mathbf{z}_2$

Head pose

Kingma and Welling, “Auto-Encoding Variational Bayes”, ICLR 2014

Variational Autoencoders: Generating Data!

32x32 CIFAR-10

Labeled Faces in the Wild

Generative Adversarial Networks (GAN)

So far...

VAEs define intractable density function with latent **z**:

$$p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$$

Cannot optimize directly, derive and optimize lower bound on likelihood instead

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What if we give up on explicitly modeling density, and just want ability to sample?

So far...

VAEs define intractable density function with latent **z**:

$$p_\theta(x) = \int p_\theta(z) p_\theta(x|z) dz$$

Cannot optimize directly, derive and optimize lower bound on likelihood instead

What if we give up on explicitly modeling density, and just want ability to sample?

GANs: don't work with any explicit density function!
Instead, take game-theoretic approach: learn to generate from training distribution through 2-player game

Generative Adversarial Networks

Ian Goodfellow et al., "Generative Adversarial Nets", NIPS 2014

Problem: Want to sample from complex, high-dimensional training distribution. No direct way to do this!

Solution: Sample from a simple distribution, e.g. random noise. Learn transformation to training distribution.

Q: What can we use to represent this complex transformation?

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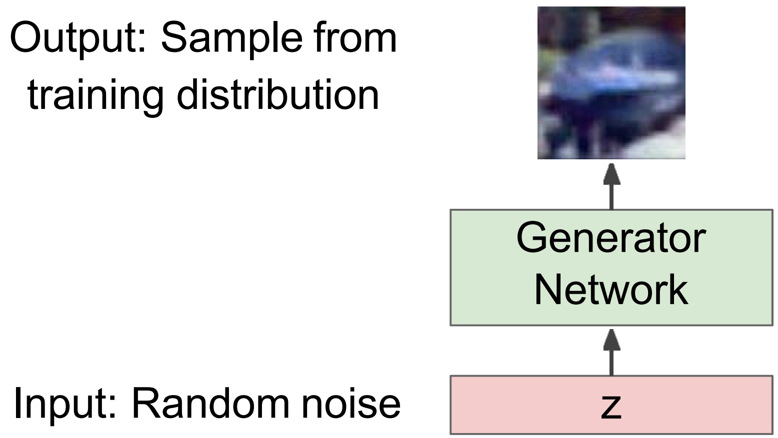
Solution: Sample from a simple distribution, e.g. random noise. Learn transformation to training distribution.

Q: What can we use to represent this complex transformation?

A: A neural network!



Training GANs: Two-player game

Ian Goodfellow et al., “Generative Adversarial Nets”, NIPS 2014

Generator network: try to fool the discriminator by generating real-looking images
Discriminator network: try to distinguish between real and fake images

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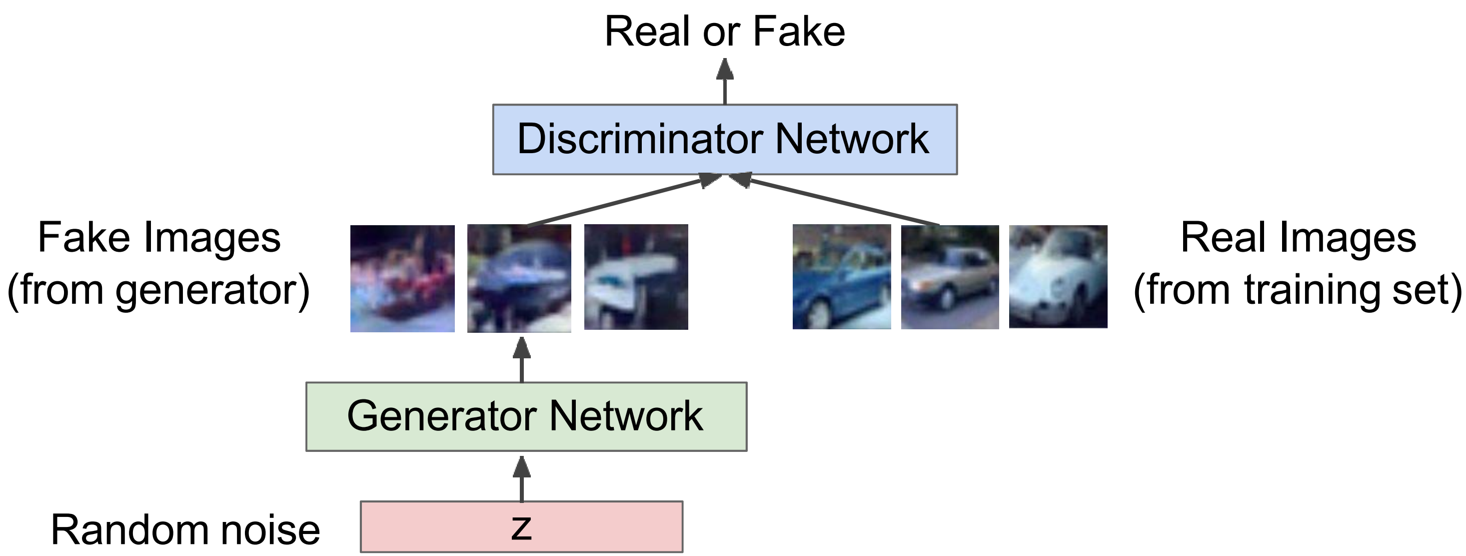

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Generator network: try to fool the discriminator by generating real-looking images
Discriminator network: try to distinguish between real and fake images

Train jointly in **minimax game**

Minimax objective function:

$$\min_{\theta_g} \max_{\theta_d} \left[\mathbb{E}_{x \sim p_{data}} \log D_{\theta_d}(x) + \mathbb{E}_{z \sim p(z)} \log(1 - D_{\theta_d}(G_{\theta_g}(z))) \right]$$

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Discriminator outputs likelihood in (0,1) of real image

Minimax objective function:

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- Discriminator (θ_d) wants to **maximize objective** such that D(x) is close to 1 (real) and D(G(z)) is close to 0 (fake)
- Generator (θ_g) wants to **minimize objective** such that D(G(z)) is close to 1 (discriminator is fooled into thinking generated G(z) is real)

Training GANs: Two-player game

Ian Goodfellow et al., "Generative Adversarial Nets", NIPS 2014

Minimax objective function:

$$\min_{\theta_g} \max_{\theta_d} \left[\mathbb{E}_{x \sim p_{data}} \log D_{\theta_d}(x) + \mathbb{E}_{z \sim p(z)} \log(1 - D_{\theta_d}(G_{\theta_g}(z))) \right]$$

Alternate between:

1. **Gradient ascent** on discriminator

$$\max_{\theta_d} \left[\mathbb{E}_{x \sim p_{data}} \log D_{\theta_d}(x) + \mathbb{E}_{z \sim p(z)} \log(1 - D_{\theta_d}(G_{\theta_g}(z))) \right]$$

2. **Gradient descent** on generator

$$\min_{\theta_g} \mathbb{E}_{z \sim p(z)} \log(1 - D_{\theta_d}(G_{\theta_g}(z)))$$

Training GANs: Two-player game

Ian Goodfellow et al., "Generative Adversarial Nets", NIPS 2014

Putting it together: GAN training algorithm

for number of training iterations **do**

  for k steps **do**

  - Sample minibatch of m noise samples $\{\boldsymbol{z}^{(1)}, \ldots, \boldsymbol{z}^{(m)}\}$ from noise prior $p_g(\boldsymbol{z})$.
  - Sample minibatch of m examples $\{\boldsymbol{x}^{(1)}, \ldots, \boldsymbol{x}^{(m)}\}$ from data generating distribution $p_{\text{data}}(\boldsymbol{x})$.
  - Update the discriminator by ascending its stochastic gradient:

$$\nabla_{\theta_d} \frac{1}{m} \sum_{i=1}^{m} \left[\log D_{\theta_d}(x^{(i)}) + \log(1 - D_{\theta_d}(G_{\theta_g}(z^{(i)}))) \right]$$

  end for

- Sample minibatch of m noise samples $\{\boldsymbol{z}^{(1)}, \ldots, \boldsymbol{z}^{(m)}\}$ from noise prior $p_g(\boldsymbol{z})$.
- Update the generator by ascending its stochastic gradient **(improved objective):**

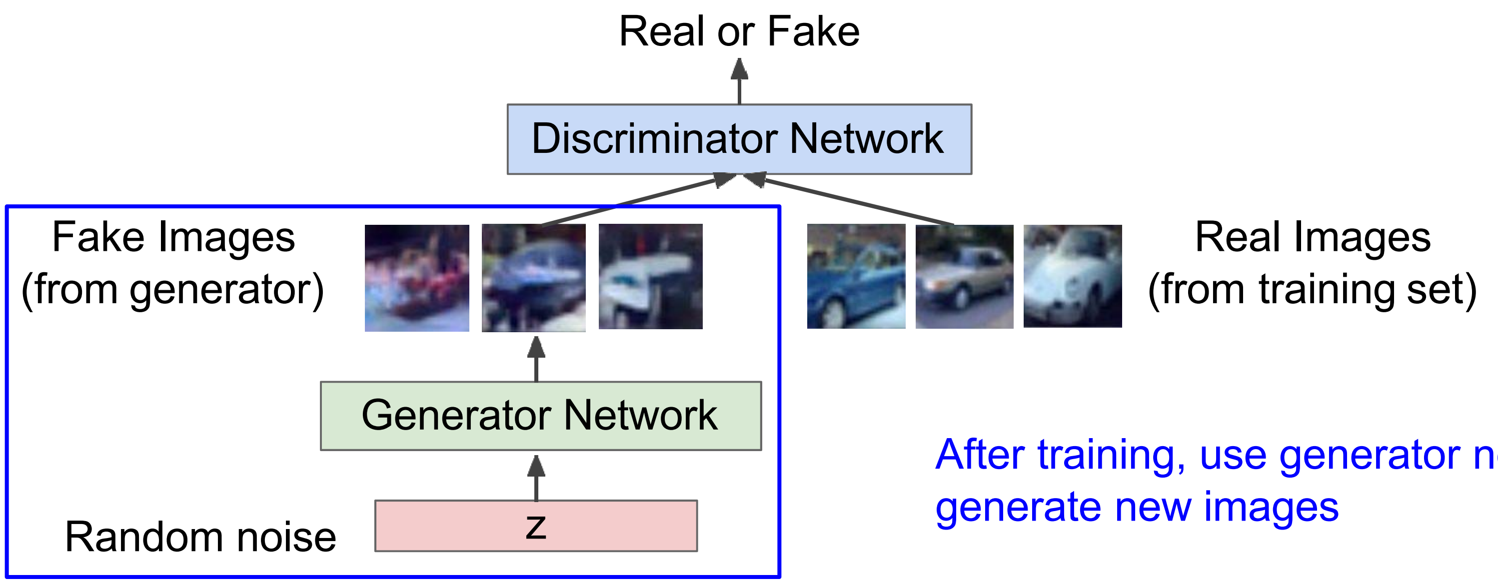
$$\nabla_{\theta_g} \frac{1}{m} \sum_{i=1}^{m} \log(D_{\theta_d}(G_{\theta_g}(z^{(i)})))$$

end for

Training GANs: Two-player game

Ian Goodfellow et al., "Generative Adversarial Nets", NIPS 2014

Generator network: try to fool the discriminator by generating real-looking images
Discriminator network: try to distinguish between real and fake images

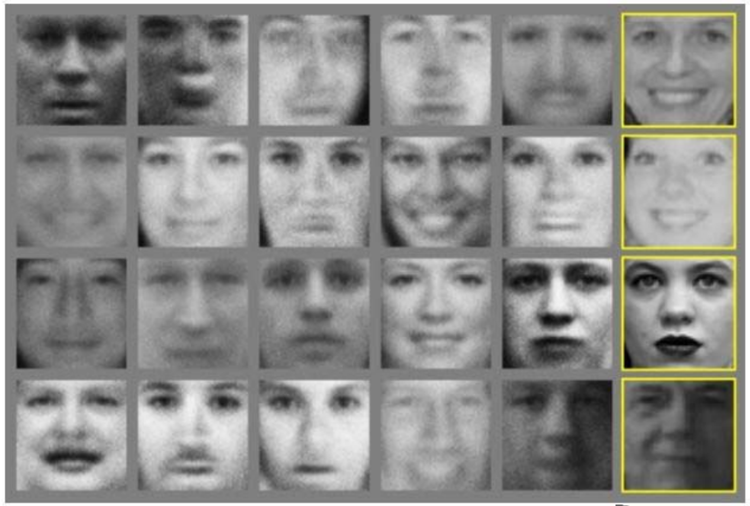


After training, use generator network to generate new images

Generative Adversarial Nets

Ian Goodfellow et al., “Generative Adversarial Nets”, NIPS 2014

Generated samples

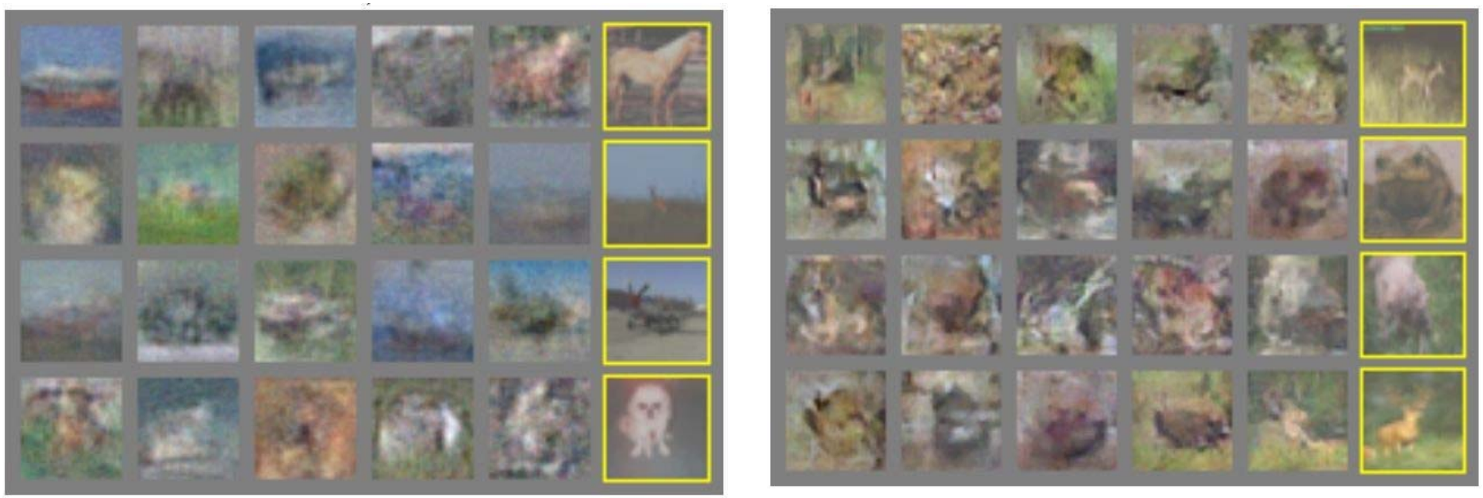


Nearest neighbor from training set

Ian Goodfellow et al., “Generative
Adversarial Nets”, NIPS 2014

Generative Adversarial Nets

Generated samples (CIFAR-10)



Nearest neighbor from training set

Generative Adversarial Nets: Convolutional Architectures

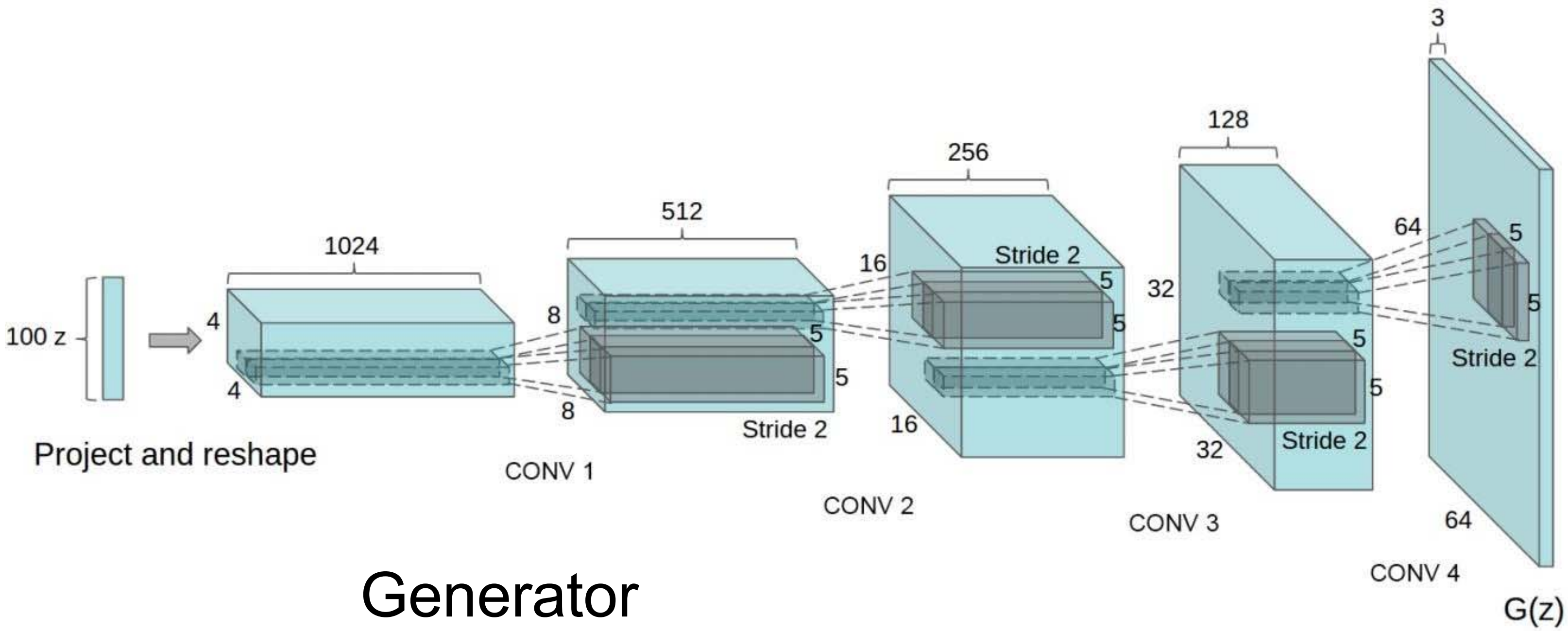
Generator is an upsampling network with fractionally-strided convolutions
Discriminator is a convolutional network

Architecture guidelines for stable Deep Convolutional GANs

- Replace any pooling layers with strided convolutions (discriminator) and fractional-strided convolutions (generator).
- Use batchnorm in both the generator and the discriminator.
- Remove fully connected hidden layers for deeper architectures.
- Use ReLU activation in generator for all layers except for the output, which uses Tanh.
- Use LeakyReLU activation in the discriminator for all layers.

Radford et al, “Unsupervised Representation Learning with Deep Convolutional Generative Adversarial Networks”, ICLR 2016

Generative Adversarial Nets: Convolutional Architectures



Generator

Radford et al, “Unsupervised Representation Learning with Deep Convolutional Generative Adversarial Networks”, ICLR 2016

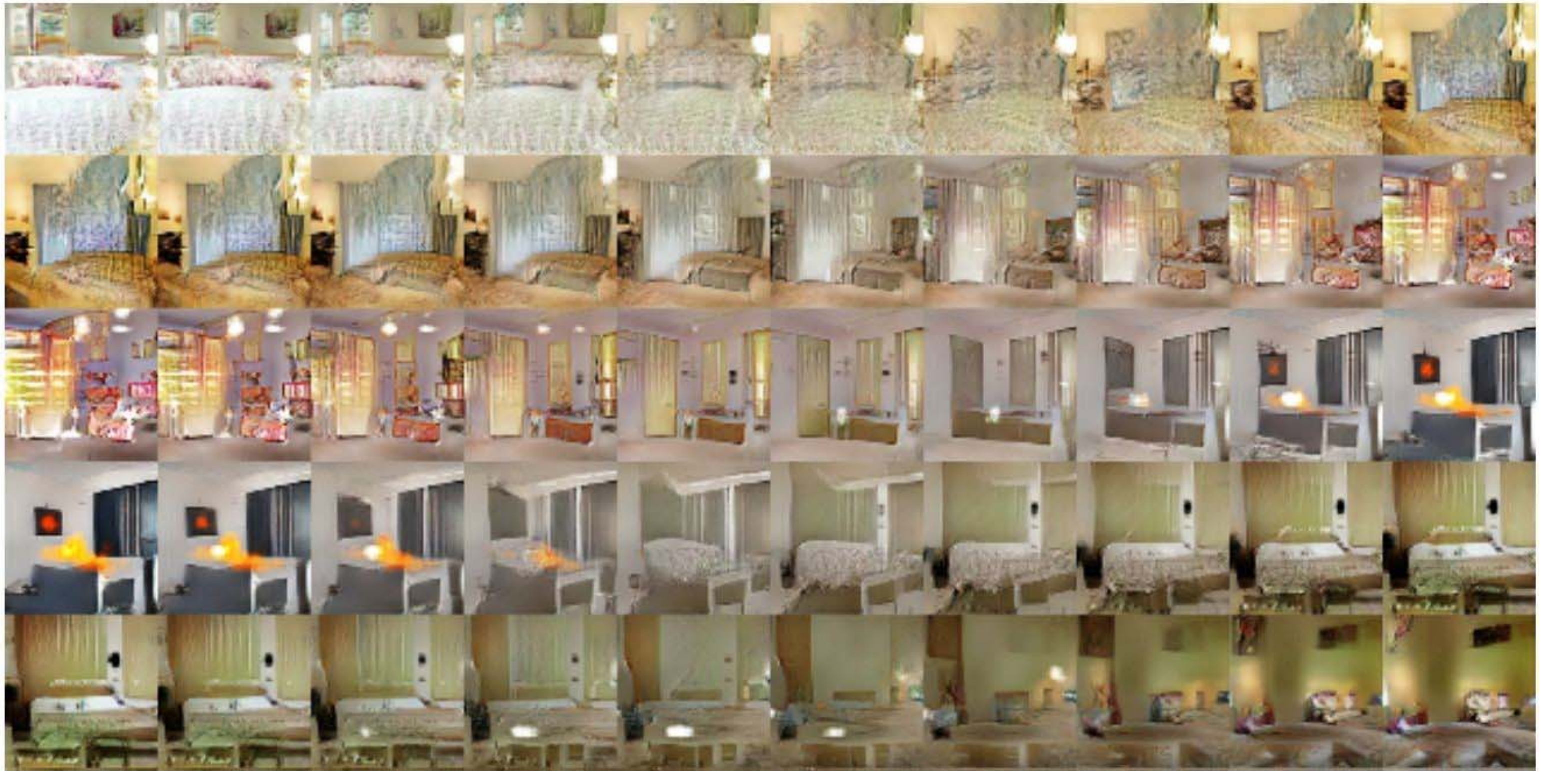
Generative Adversarial Nets: Convolutional Architectures

Samples from the model look amazing!

Radford et al, ICLR 2016

Generative Adversarial Nets: Convolutional Architectures

Interpolating between random points in laten space



Radford et al,
ICLR 2016

Generative Adversarial Nets: Interpretable Vector Math

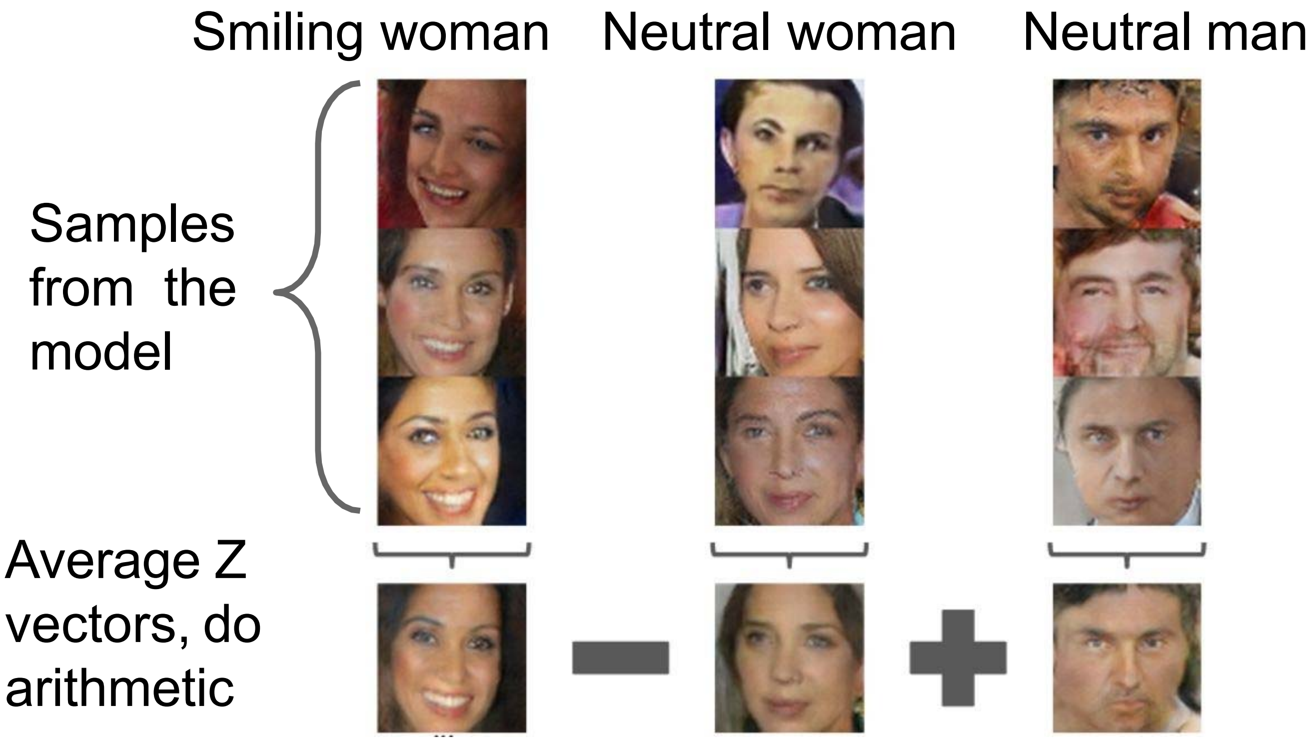
Radford et al, ICLR 2016

Smiling woman   Neutral woman   Neutral man

Samples from the model

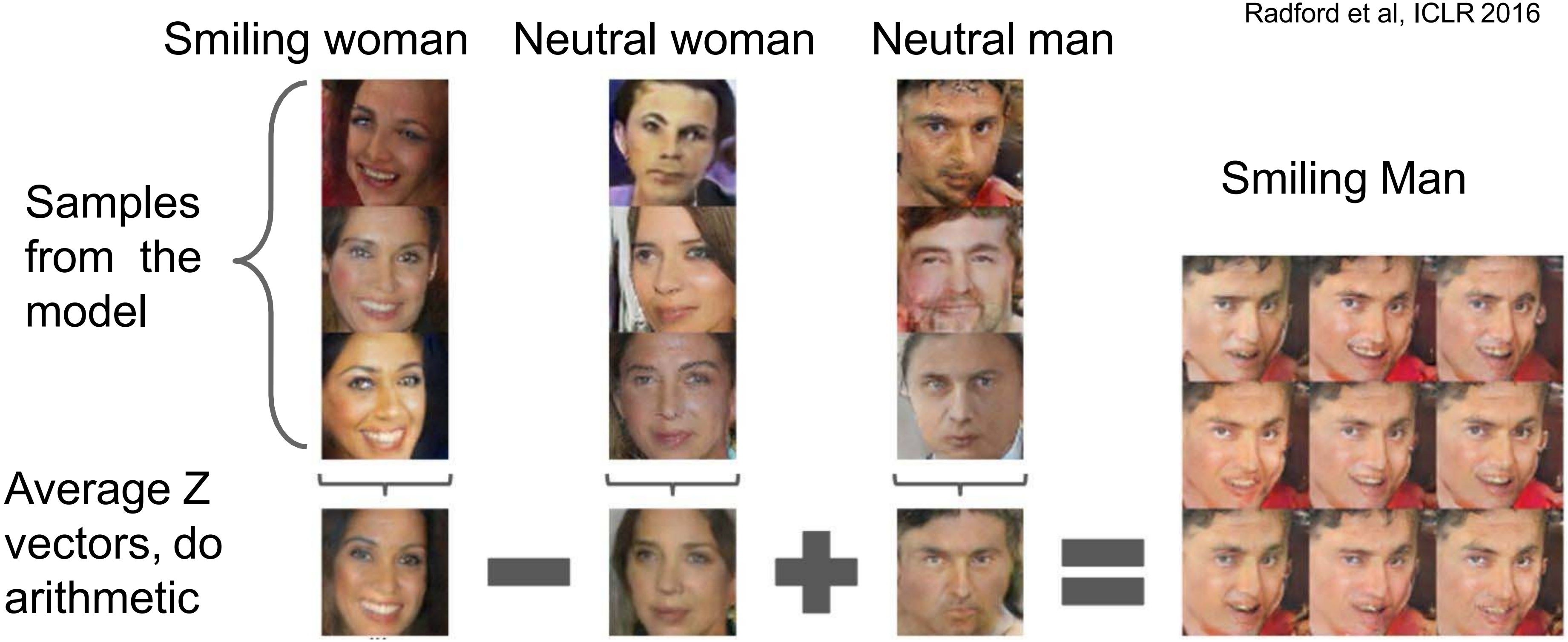
Generative Adversarial Nets: Interpretable Vector Math

Radford et al, ICLR 2016

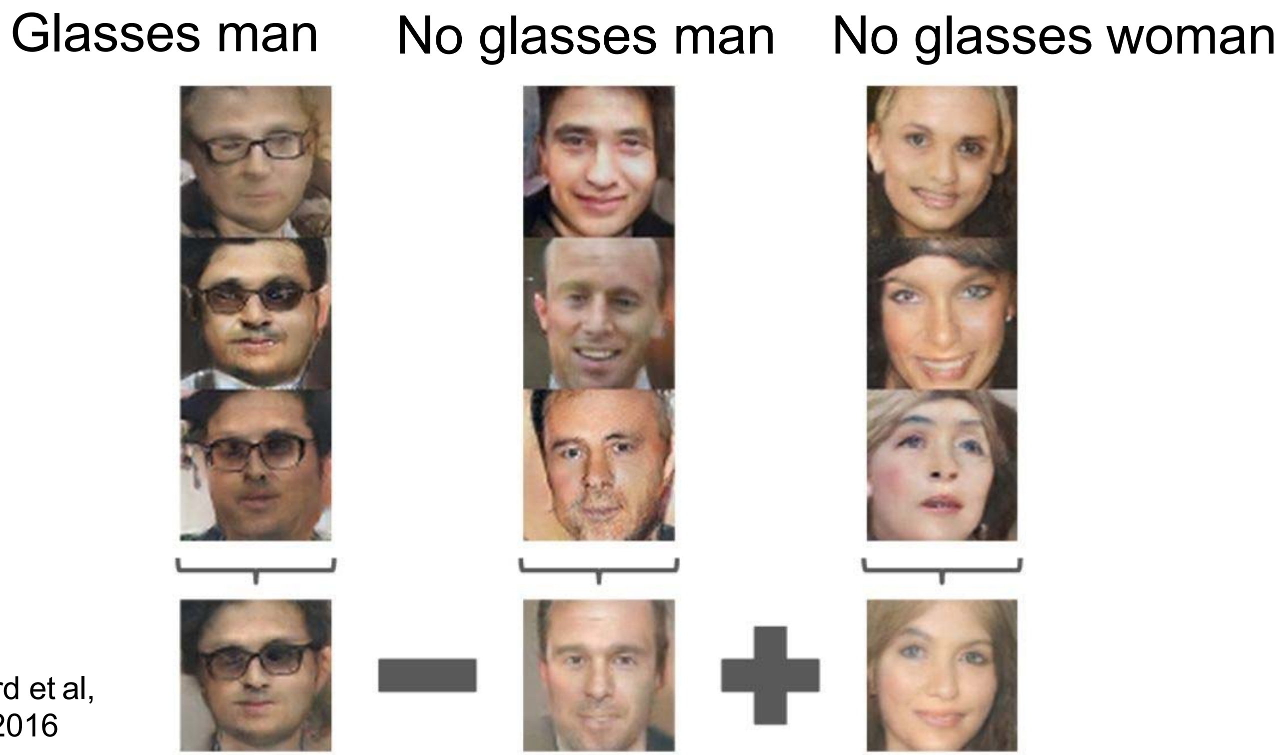


Generative Adversarial Nets: Interpretable Vector Math

Radford et al, ICLR 2016



Generative Adversarial Nets: Interpretable Vector Math



Radford et al,
ICLR 2016

Generative Adversarial Nets: Interpretable Vector Math

Radford et al, ICLR 2016

“The GAN Zoo”

- GAN - Generative Adversarial Networks
- 3D-GAN - Learning a Probabilistic Latent Space of Object Shapes via 3D Generative-Adversarial Modeling
- acGAN - Face Aging With Conditional Generative Adversarial Networks
- AC-GAN - Conditional Image Synthesis With Auxiliary Classifier GANs
- AdaGAN - AdaGAN: Boosting Generative Models
- AEGAN - Learning Inverse Mapping by Autoencoder based Generative Adversarial Nets
- AffGAN - Amortised MAP Inference for Image Super-resolution
- AL-CGAN - Learning to Generate Images of Outdoor Scenes from Attributes and Semantic Layouts
- ALI - Adversarially Learned Inference
- AM-GAN - Generative Adversarial Nets with Labeled Data by Activation Maximization
- AnoGAN - Unsupervised Anomaly Detection with Generative Adversarial Networks to Guide Marker Discovery
- ArtGAN - ArtGAN: Artwork Synthesis with Conditional Categorial GANs
- b-GAN - b-GAN: Unified Framework of Generative Adversarial Networks
- Bayesian GAN - Deep and Hierarchical Implicit Models
- BEGAN - BEGAN: Boundary Equilibrium Generative Adversarial Networks
- BiGAN - Adversarial Feature Learning
- BS-GAN - Boundary-Seeking Generative Adversarial Networks
- CGAN - Conditional Generative Adversarial Nets
- CaloGAN - CaloGAN: Simulating 3D High Energy Particle Showers in Multi-Layer Electromagnetic Calorimeters with Generative Adversarial Networks
- CCGAN - Semi-Supervised Learning with Context-Conditional Generative Adversarial Networks
- CatGAN - Unsupervised and Semi-supervised Learning with Categorical Generative Adversarial Networks
- CoGAN - Coupled Generative Adversarial Networks
- Context-RNN-GAN - Contextual RNN-GANs for Abstract Reasoning Diagram Generation
- C-RNN-GAN - C-RNN-GAN: Continuous recurrent neural networks with adversarial training
- CS-GAN - Improving Neural Machine Translation with Conditional Sequence Generative Adversarial Nets
- CVAE-GAN - CVAE-GAN: Fine-Grained Image Generation through Asymmetric Training
- CycleGAN - Unpaired Image-to-Image Translation using Cycle-Consistent Adversarial Networks
- DTN - Unsupervised Cross-Domain Image Generation
- DCGAN - Unsupervised Representation Learning with Deep Convolutional Generative Adversarial Networks
- DiscoGAN - Learning to Discover Cross-Domain Relations with Generative Adversarial Networks
- DR-GAN - Disentangled Representation Learning GAN for Pose-Invariant Face Recognition
- DualGAN - DualGAN: Unsupervised Dual Learning for Image-to-Image Translation
- EBGAN - Energy-based Generative Adversarial Network
- f-GAN - f-GAN: Training Generative Neural Samplers using Variational Divergence Minimization
- FF-GAN - Towards Large-Pose Face Frontalization in the Wild
- GAWWN - Learning What and Where to Draw
- GeneGAN - GeneGAN: Learning Object Transfiguration and Attribute Subspace from Unpaired Data
- Geometric GAN - Geometric GAN
- GoGAN - Gang of GANs: Generative Adversarial Networks with Maximum Margin Ranking
- GP-GAN - GP-GAN: Towards Realistic High-Resolution Image Blending
- IAN - Neural Photo Editing with Introspective Adversarial Networks
- iGAN - Generative Visual Manipulation on the Natural Image Manifold
- IcGAN - Invertible Conditional GANs for image editing
- ID-CGAN - Image De-raining Using a Conditional Generative Adversarial Network
- Improved GAN - Improved Techniques for Training GANs
- InfoGAN - InfoGAN: Interpretable Representation Learning by Information Maximizing Generative Adversarial Nets
- LAGAN - Learning Particle Physics by Example: Location-Aware Generative Adversarial Networks for Physics Synthesis
- LAPGAN - Deep Generative Image Models using a Laplacian Pyramid of Adversarial Networks

https://github.com/hindupuravinash/the-gan-zoo

“The GAN Zoo”

See also: https://github.com/soumith/ganhacks for tips and tricks for trainings GANs

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GANs

Don't work with an explicit density function
Take game-theoretic approach: learn to generate from training distribution through 2-player game

Pros:
- Beautiful, state-of-the-art samples!

Cons:
- Trickier / more unstable to train
- Can't solve inference queries such as p(x), p(z|x)

Active areas of research:
- Better loss functions, more stable training (Wasserstein GAN, LSGAN, many others)
- Conditional GANs, GANs for all kinds of applications