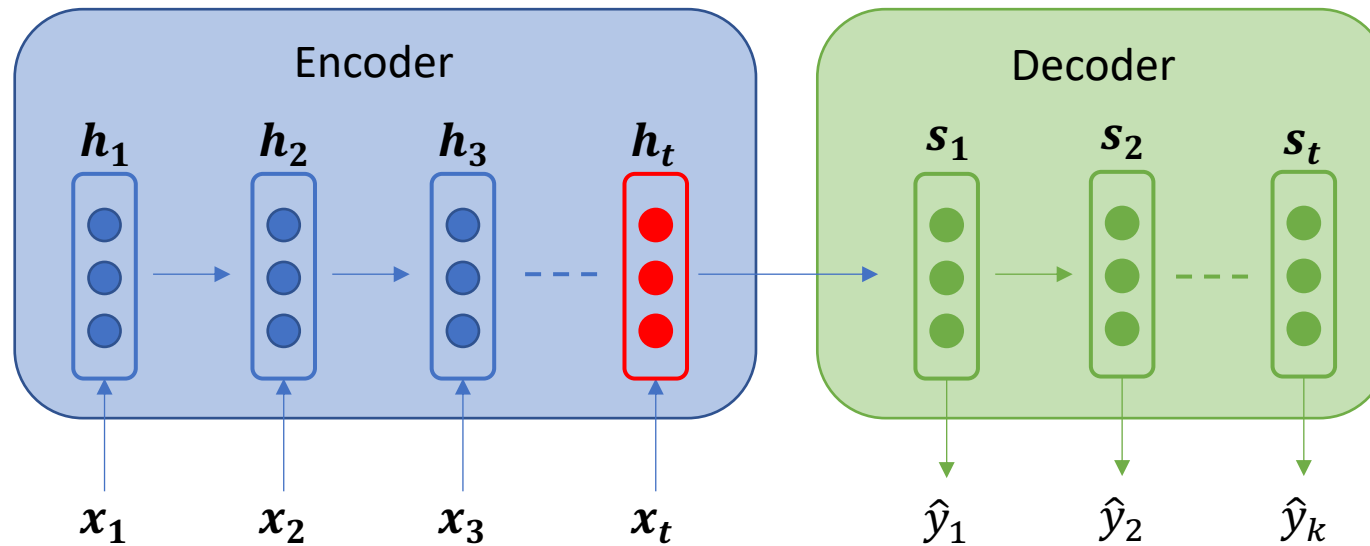


EE7207 Week 9

Attention Mechanisms and Transformers

Bottleneck of encoder-decoder network

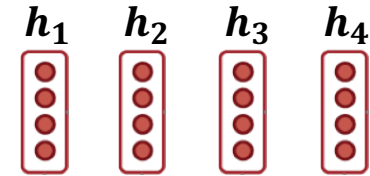
- Encoding of input sequence: a fixed length vector h_t
- Need to capture all necessary information of input sequence
- Information bottleneck, especially when input sequence is long



Attention: thinking process

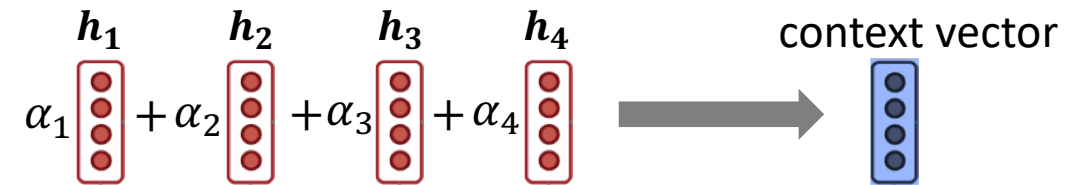
How to solve the bottleneck problem?

Instead of only using only h_4 , let's use all encoder hidden states!



How do we deal with variable length input sequence?

Let's do a weighted sum of all encoder hidden states!



How do we get the weights α_i ?

Step 1: dot product $s_t \circ h_1 = score_1$

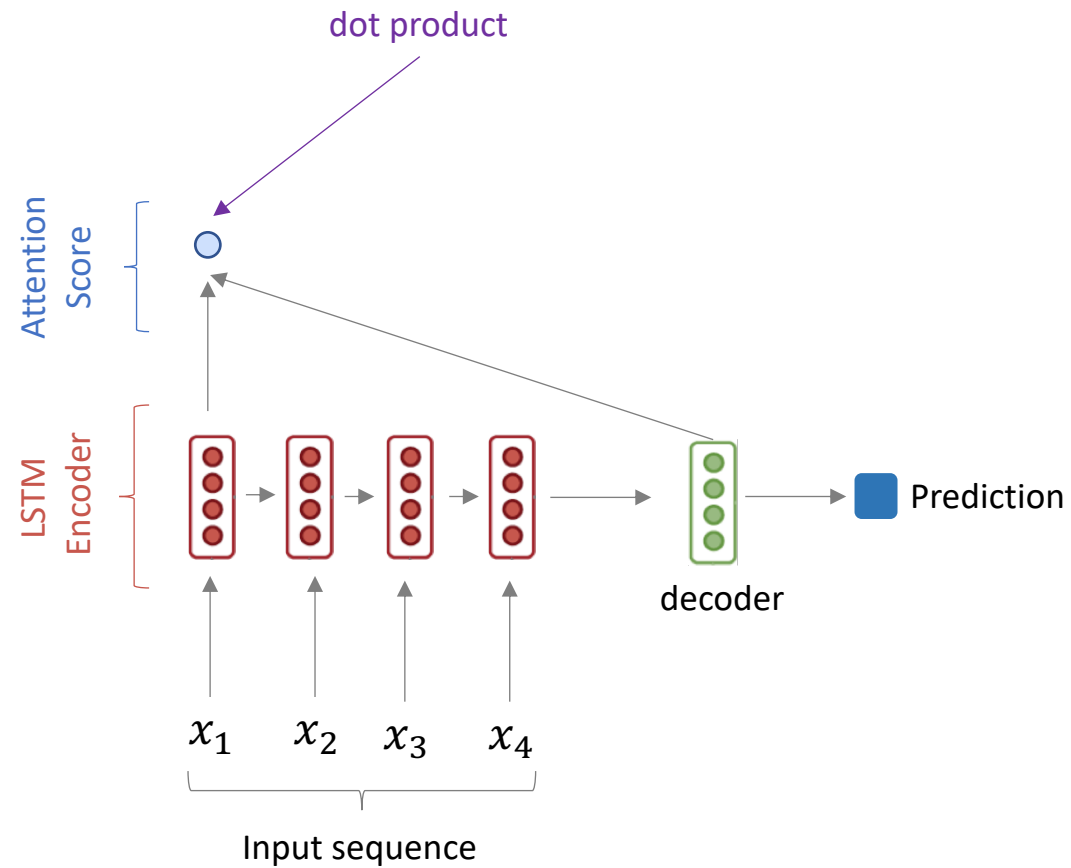
$s_t \circ h_2 = score_2$

$s_t \circ h_3 = score_3$

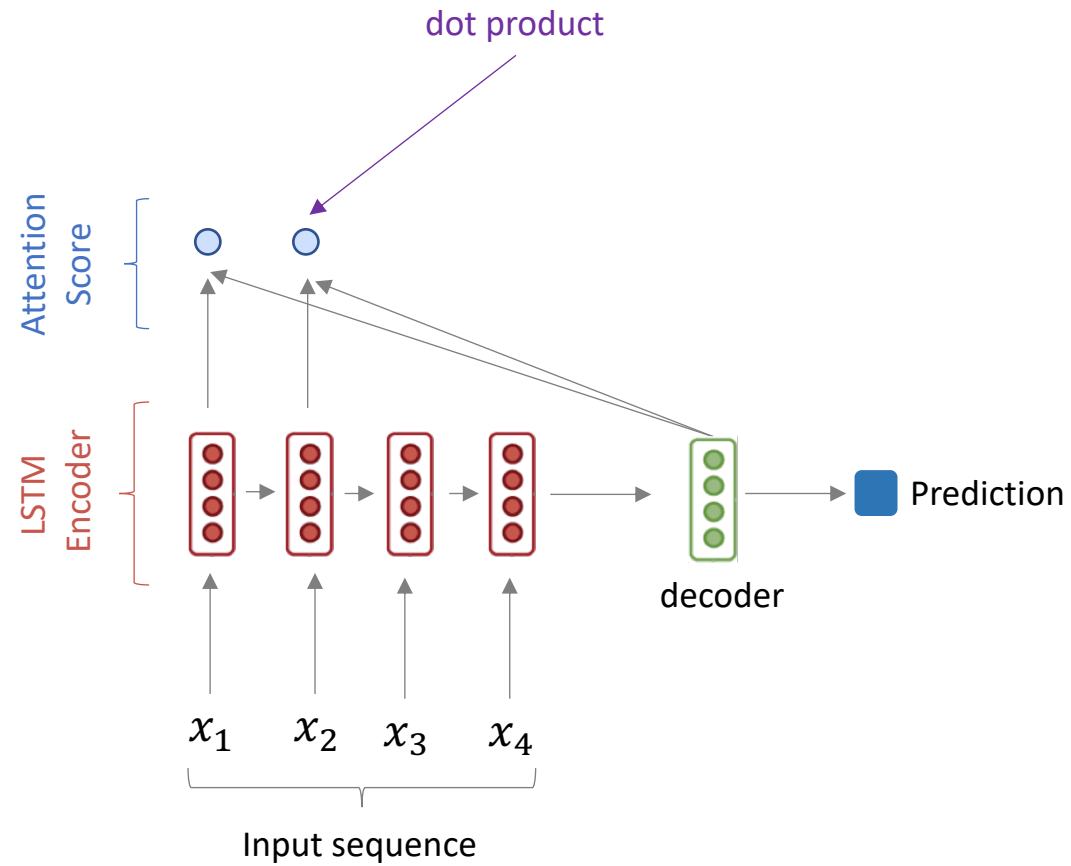
$s_t \circ h_4 = score_4$

Step 2: softmax
$$\alpha_i = \frac{\exp(score_i)}{\sum_{j=1}^4 score_j}$$

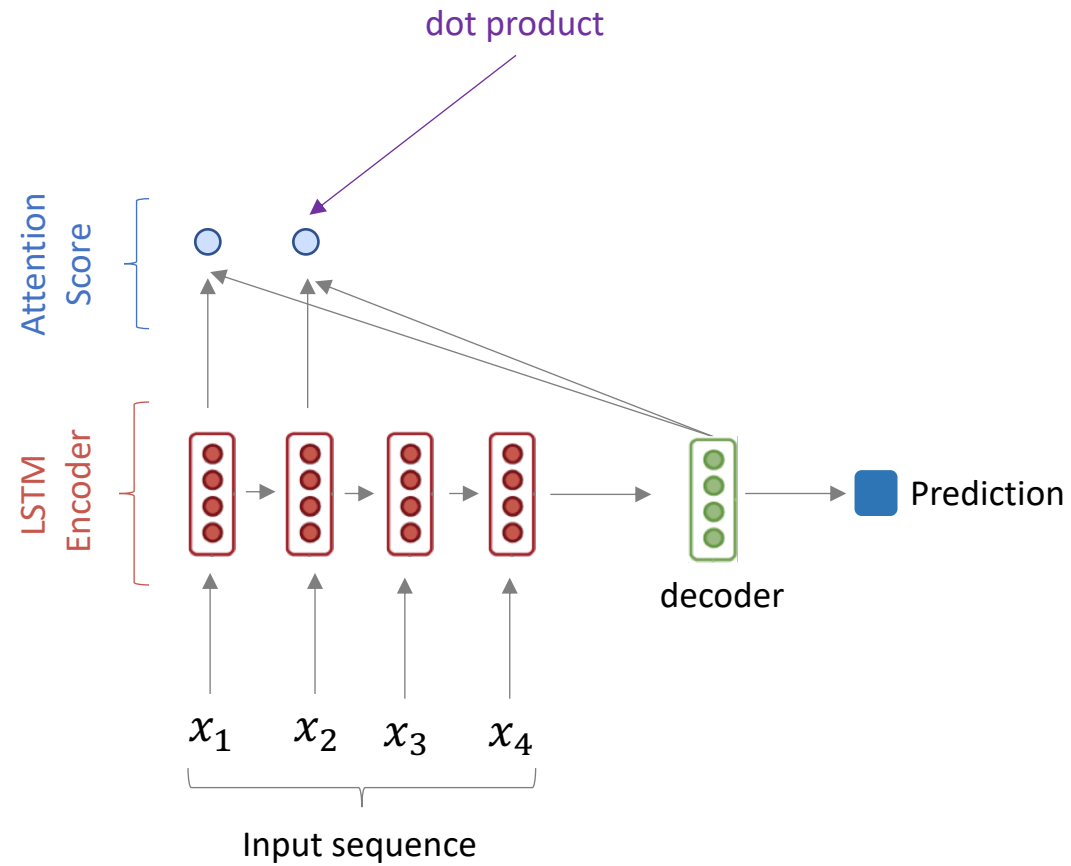
LSTM with attention



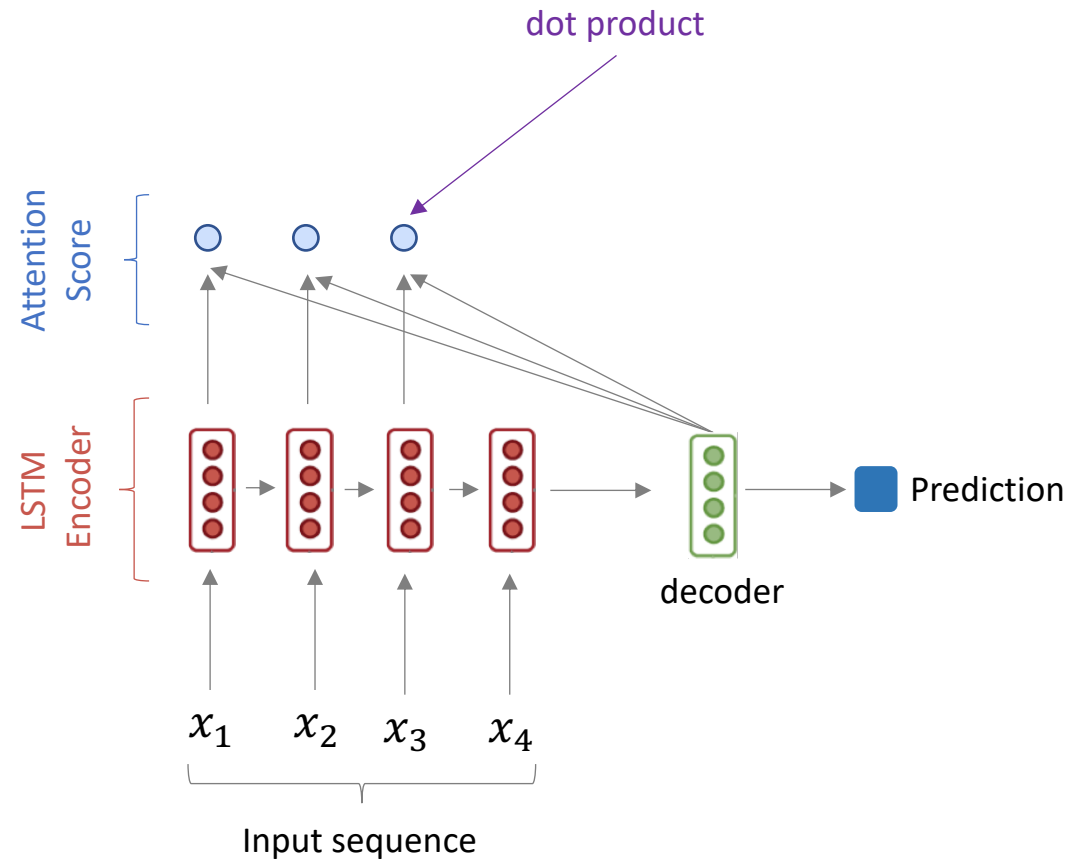
LSTM with attention



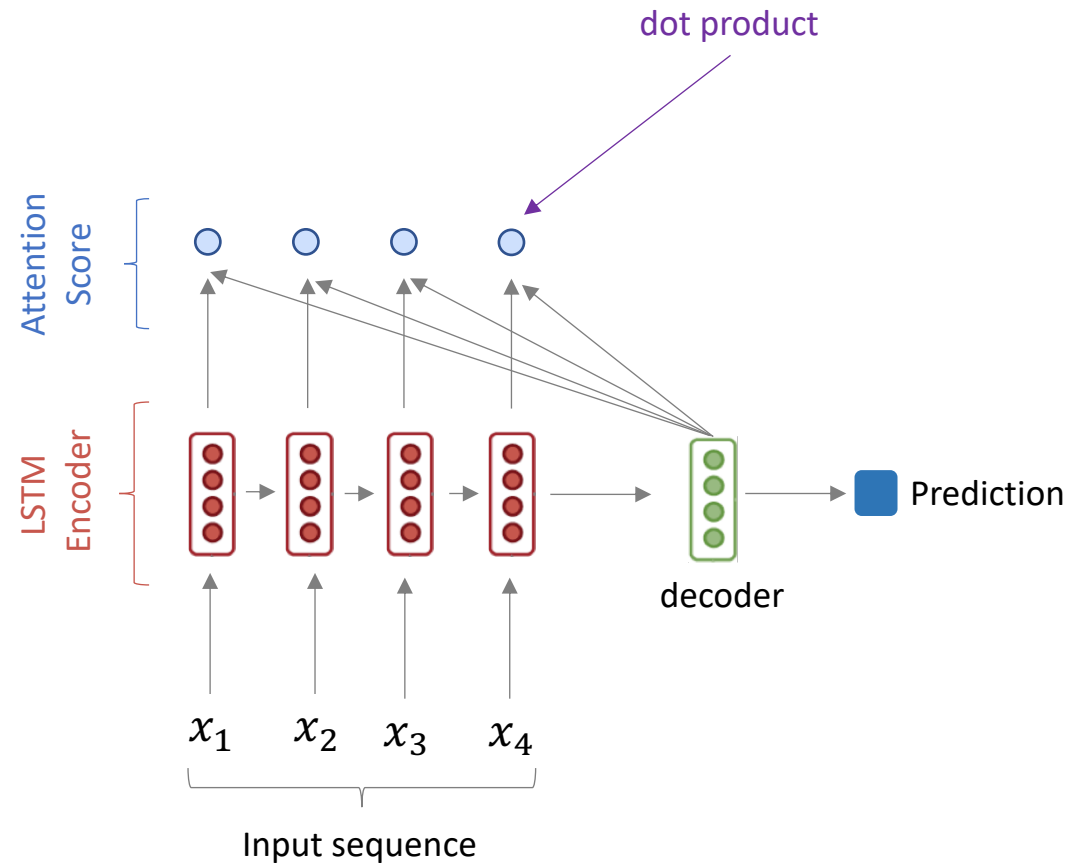
LSTM with attention



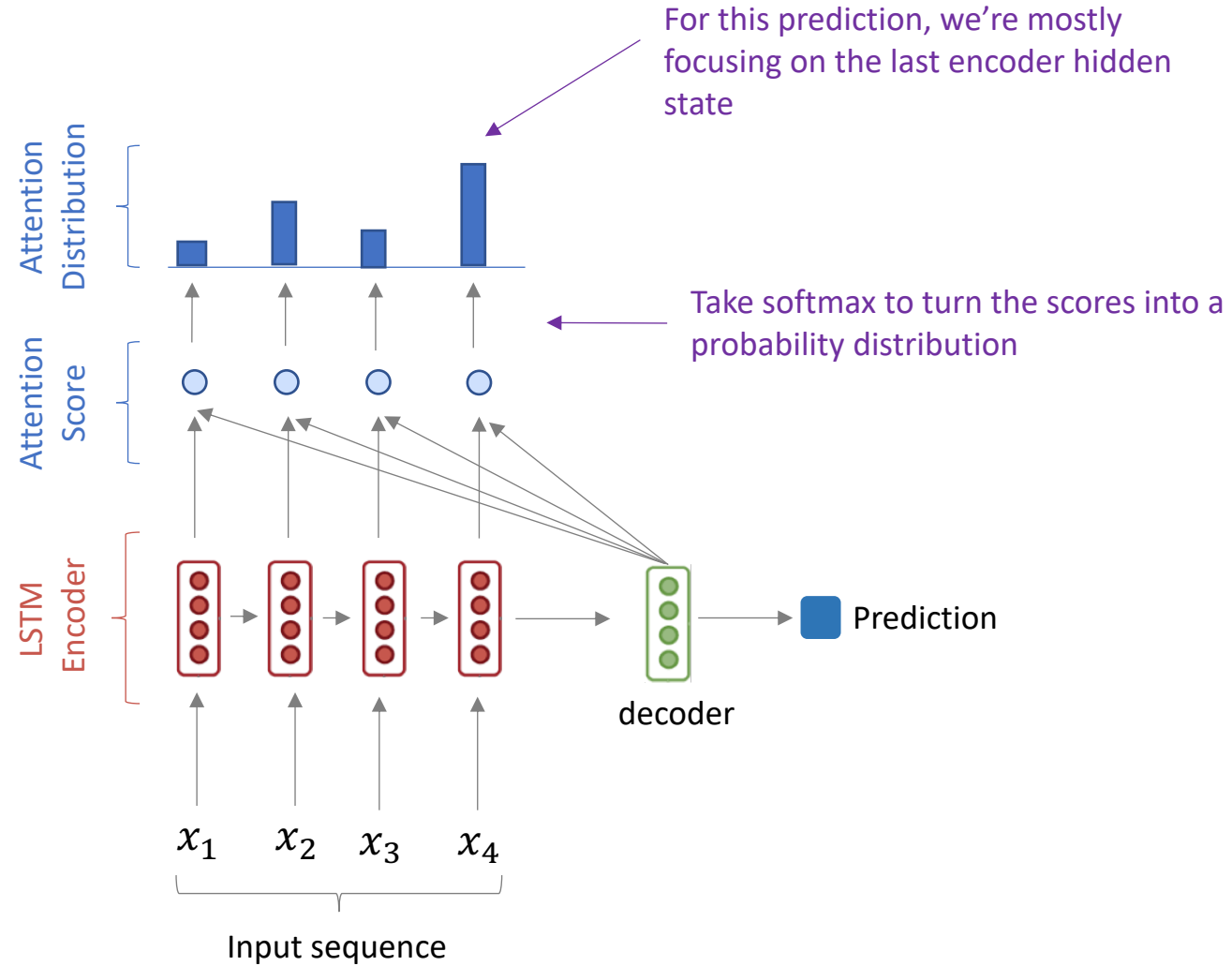
LSTM with attention



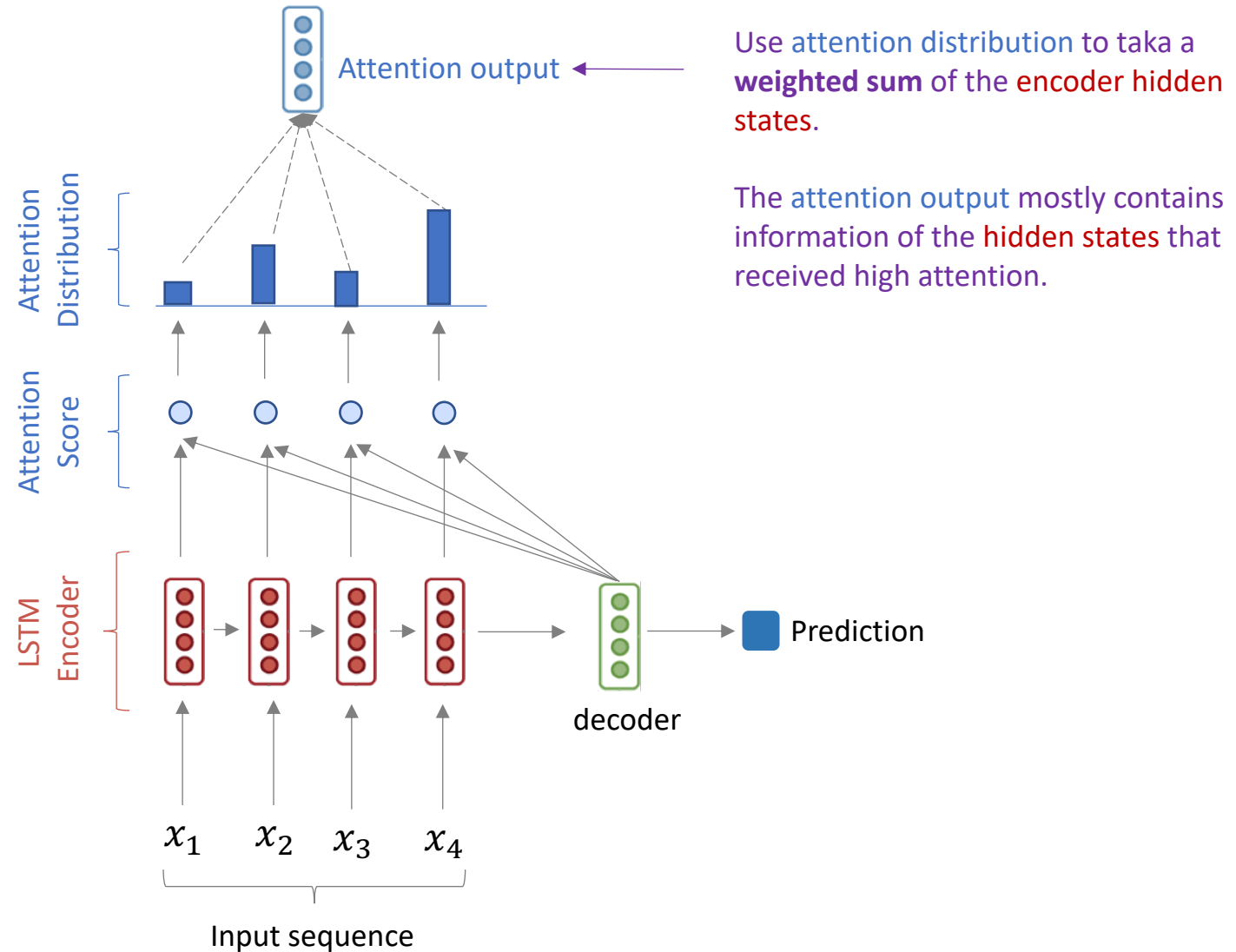
LSTM with attention



LSTM with attention



LSTM with attention



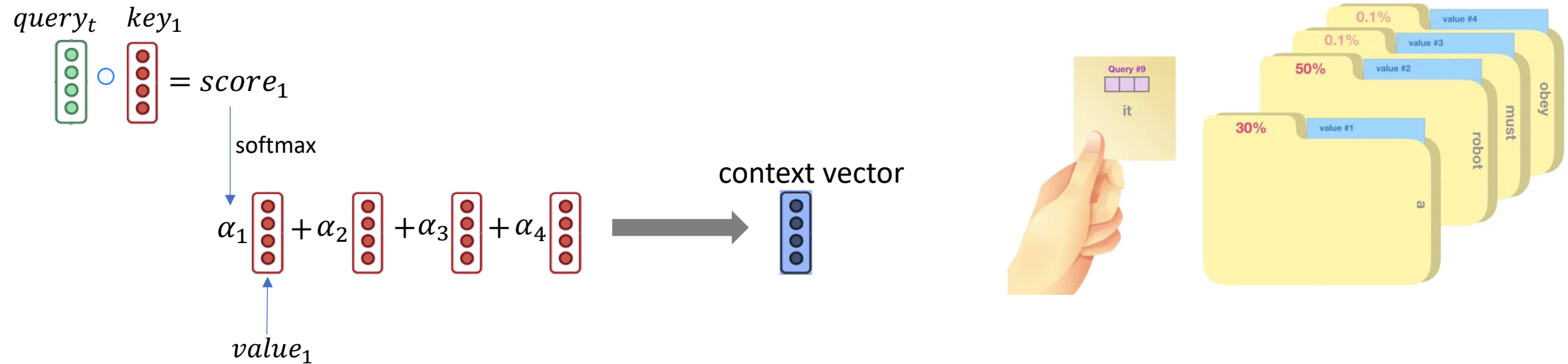
Another way to compute attention score: key-query-value attention

Inspired by information retrieval

Limitation of dot-product attention:

- What if the dimensions of decoder hidden states and encoder hidden states differ
- Question for later: Can dot-product attention support multi-head attentions?

Key-Query-Value attention:



Transformers

Attention Is All You Need

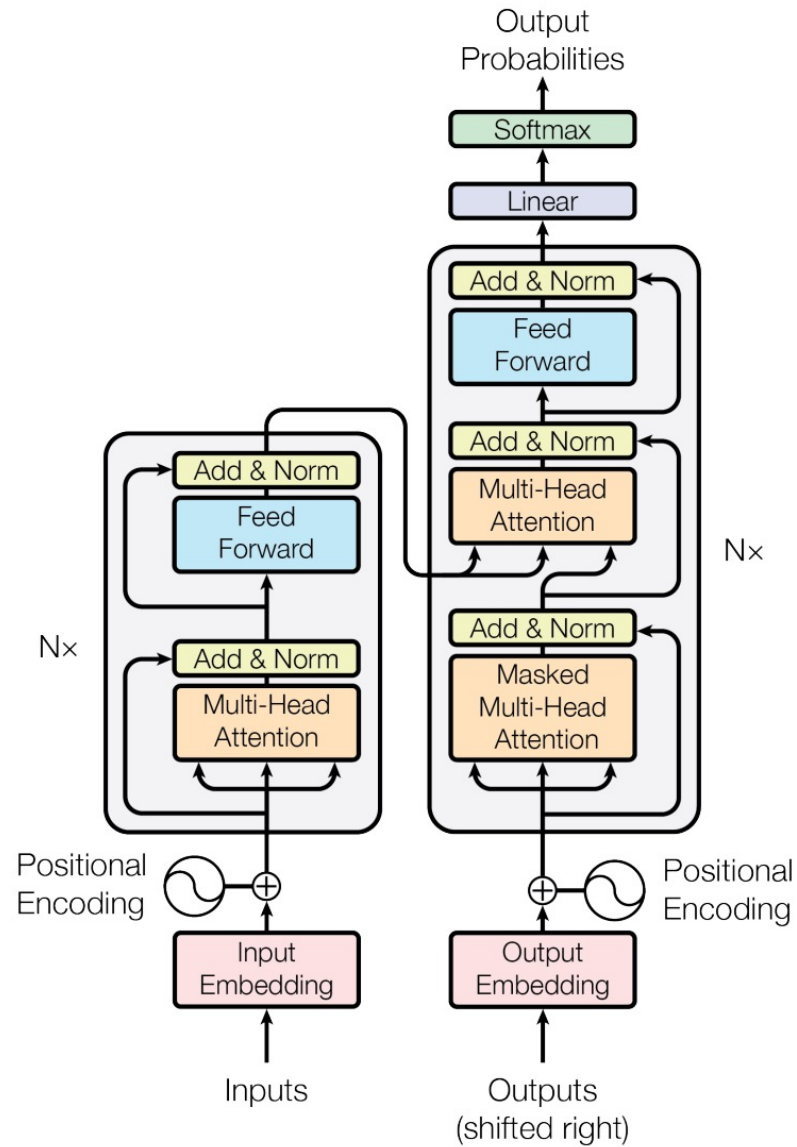
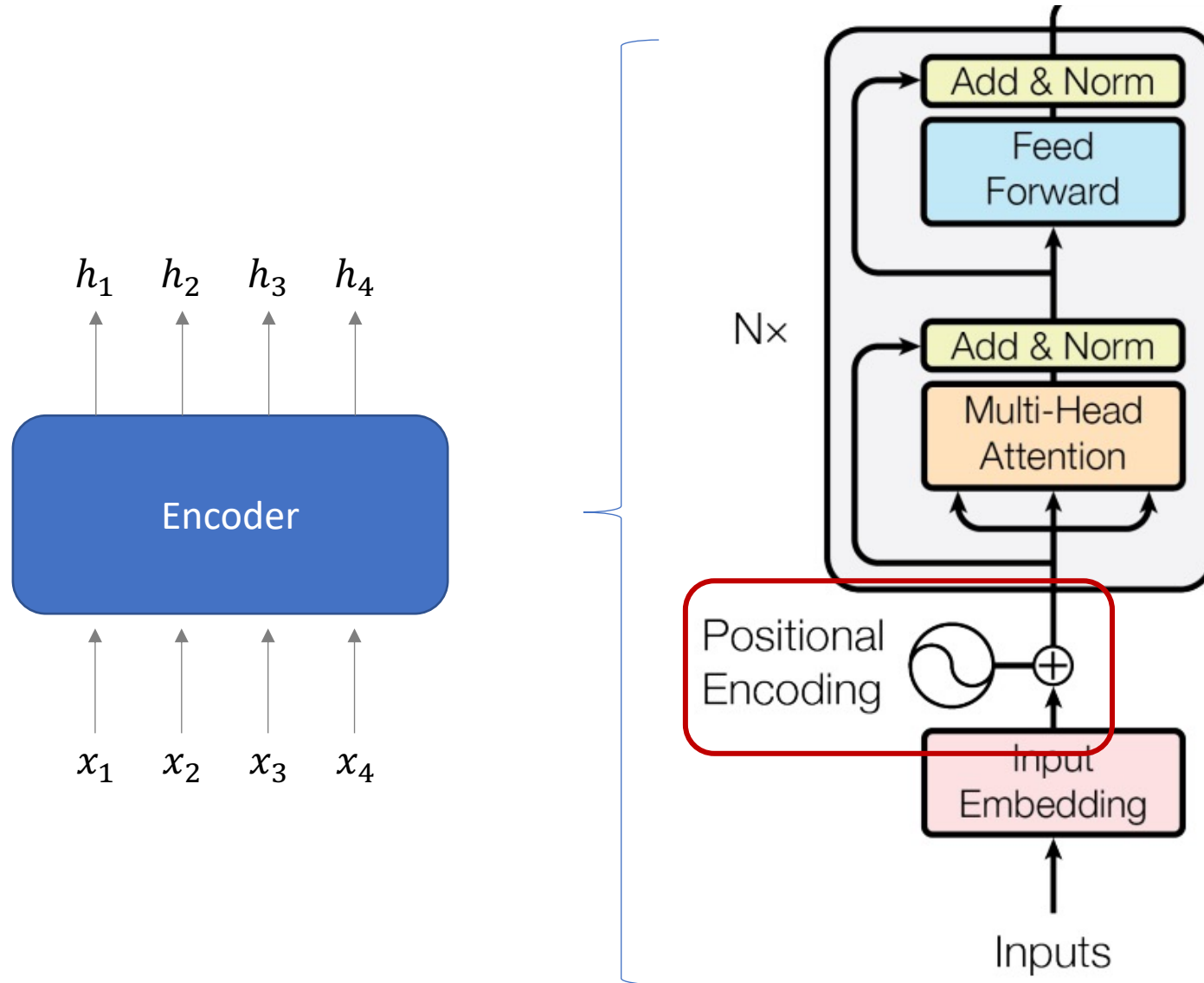
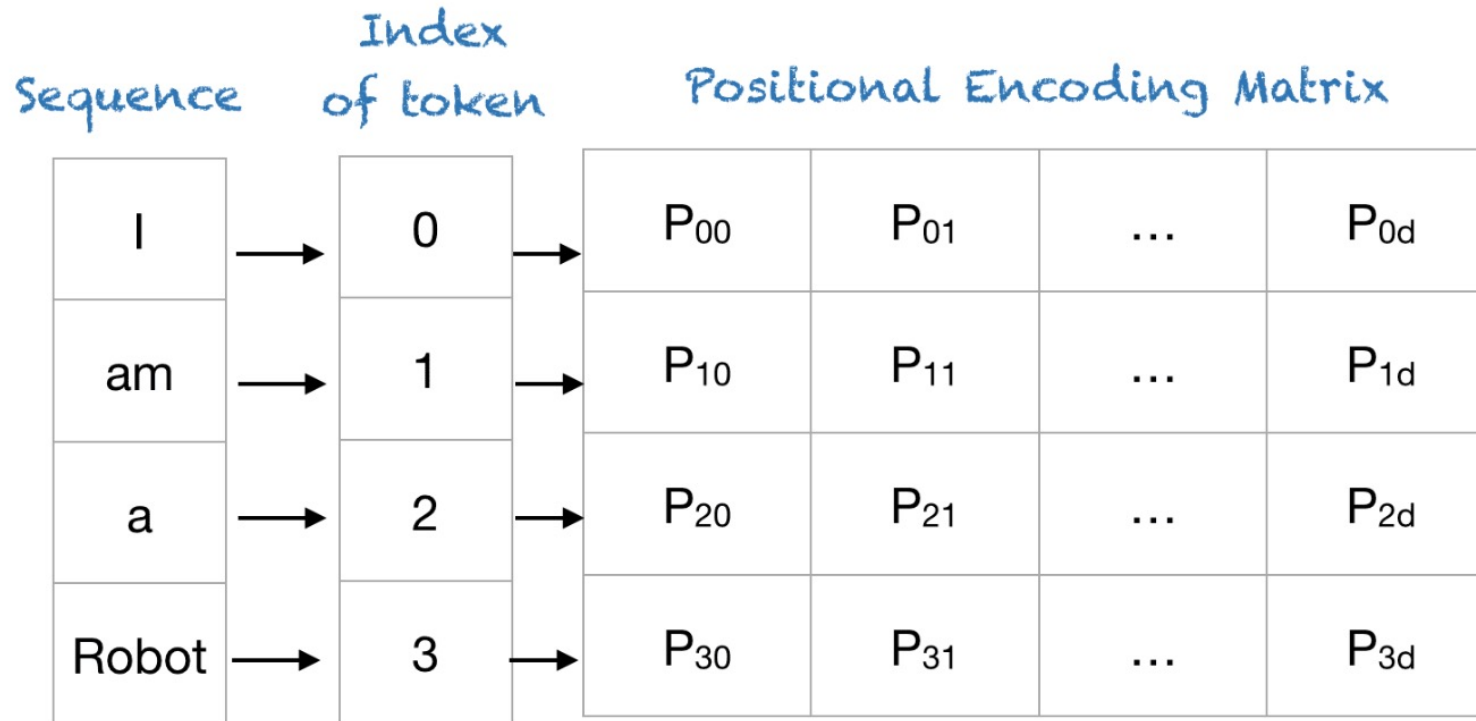


Figure 1: The Transformer - model architecture.

Encoder



Positional Encoding



Positional Encoding Matrix for the sequence 'I am a robot'

Positional Encoding

$$P(k, 2i) = \sin\left(\frac{k}{n^{2i/d}}\right)$$
$$P(k, 2i + 1) = \cos\left(\frac{k}{n^{2i/d}}\right)$$

input sequence of length

Here:

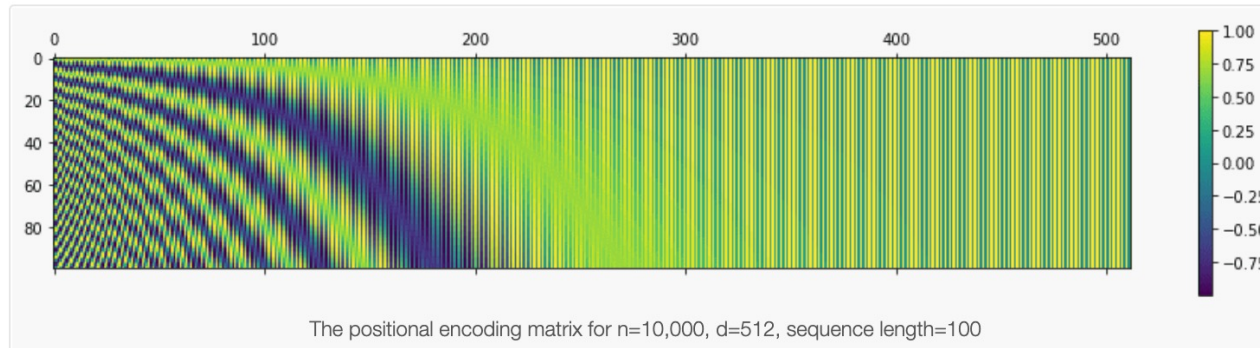
k : Position of an object in the input sequence, $0 \leq k < L/2$

d : Dimension of the output embedding space

$P(k, j)$: Position function for mapping a position k in the input sequence to index (k, j) of the positional matrix

n : User-defined scalar, set to 10,000 by the authors of [Attention Is All You Need](#).

i : Used for mapping to column indices $0 \leq i < d/2$, with a single value of i maps to both sine and cosine functions

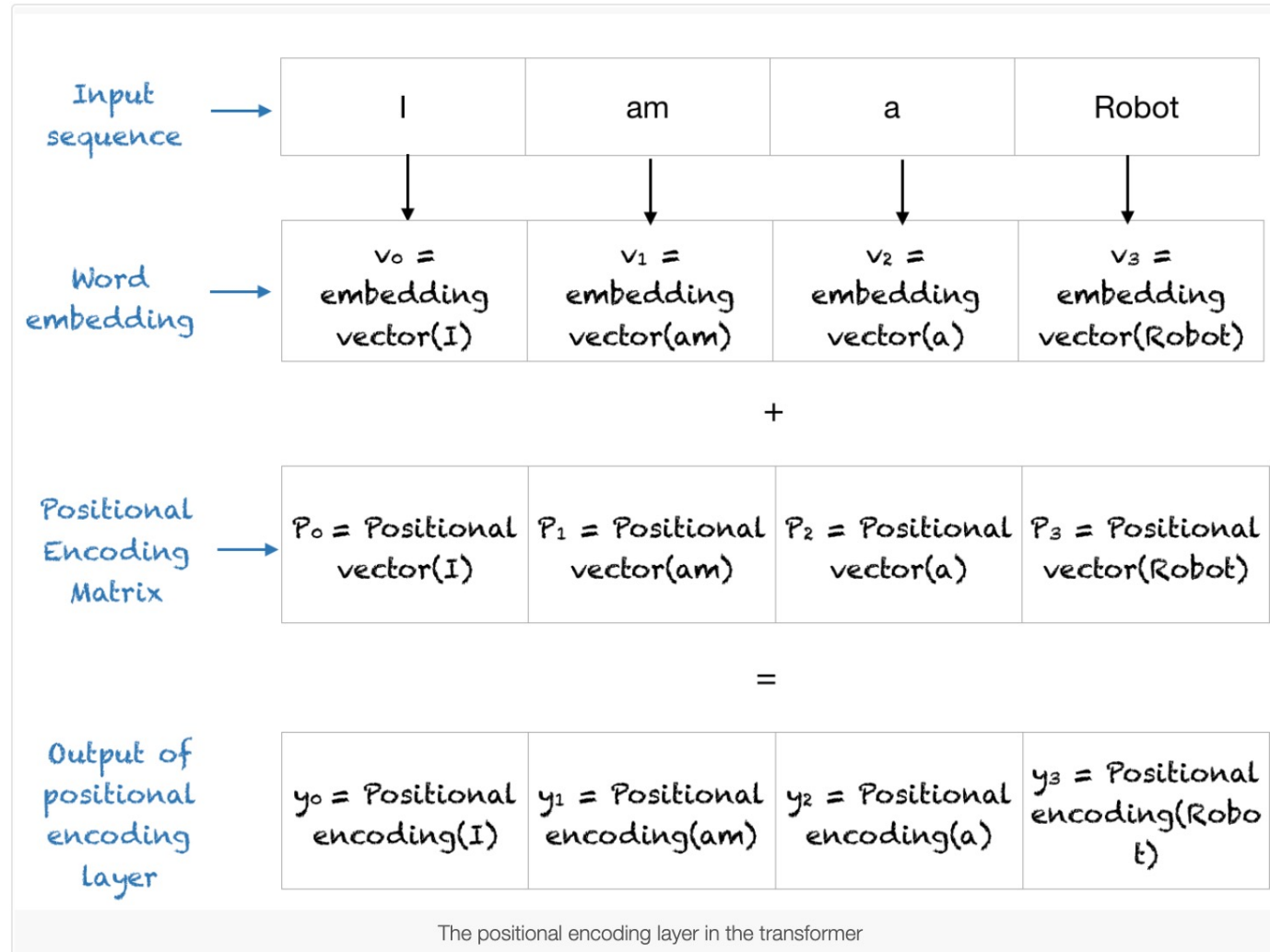


Positional Encoding

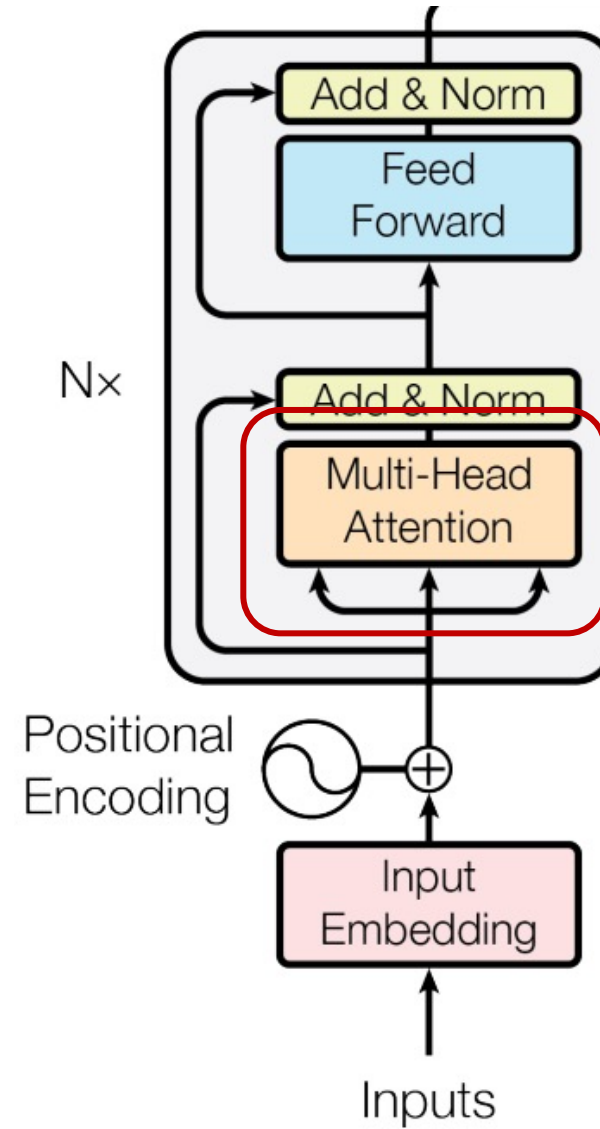
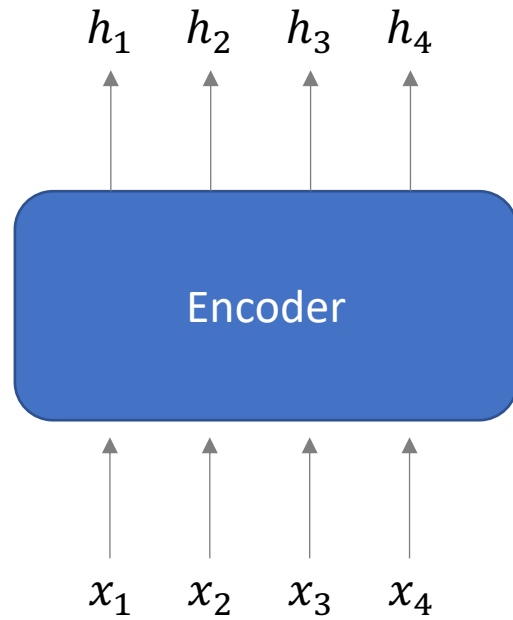
Sequence	Index of token, k	Positional Encoding Matrix with $d=4$, $n=100$			
		$i=0$	$i=0$	$i=1$	$i=1$
I	0	$P_{00}=\sin(0)$ = 0	$P_{01}=\cos(0)$ = 1	$P_{02}=\sin(0)$ = 0	$P_{03}=\cos(0)$ = 1
am	1	$P_{10}=\sin(1/1)$ = 0.84	$P_{11}=\cos(1/1)$ = 0.54	$P_{12}=\sin(1/10)$ = 0.10	$P_{13}=\cos(1/10)$ = 1.0
a	2	$P_{20}=\sin(2/1)$ = 0.91	$P_{21}=\cos(2/1)$ = -0.42	$P_{22}=\sin(2/10)$ = 0.20	$P_{23}=\cos(2/10)$ = 0.98
Robot	3	$P_{30}=\sin(3/1)$ = 0.14	$P_{31}=\cos(3/1)$ = -0.99	$P_{32}=\sin(3/10)$ = 0.30	$P_{33}=\cos(3/10)$ = 0.96

Positional Encoding Matrix for the sequence 'I am a robot'

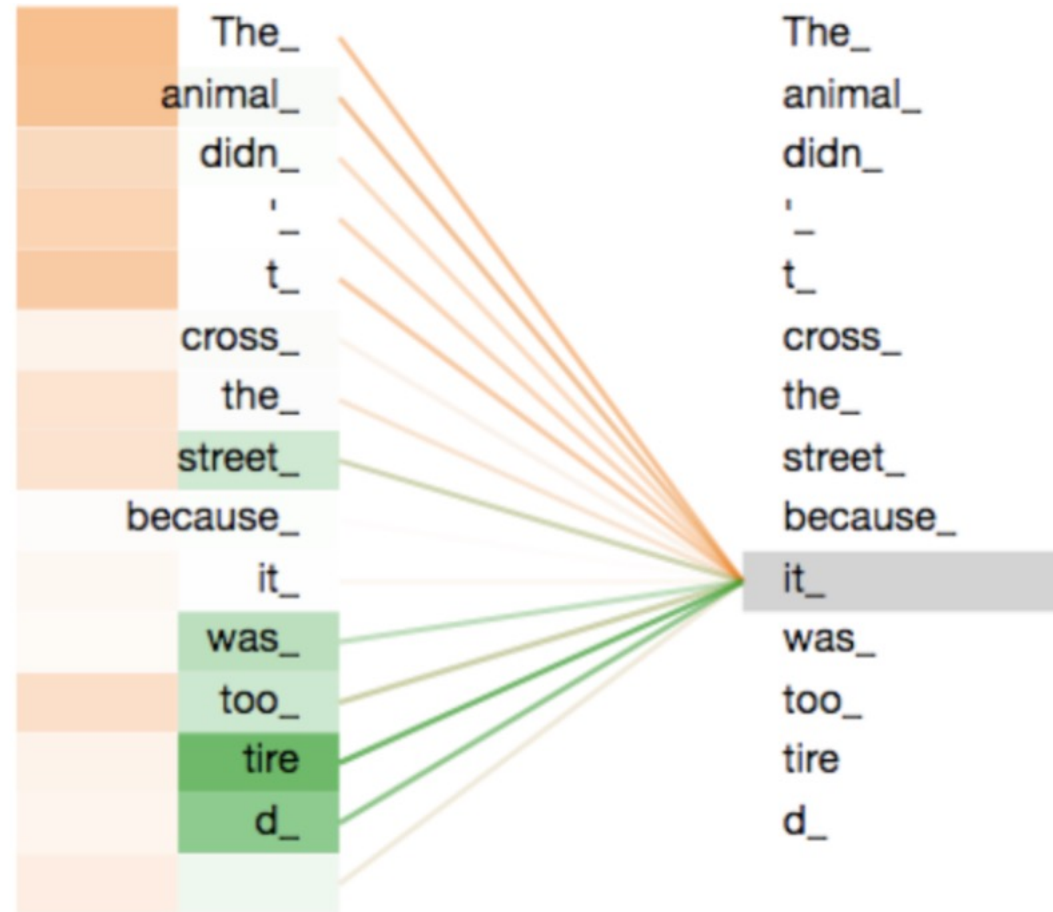
Positional Encoding



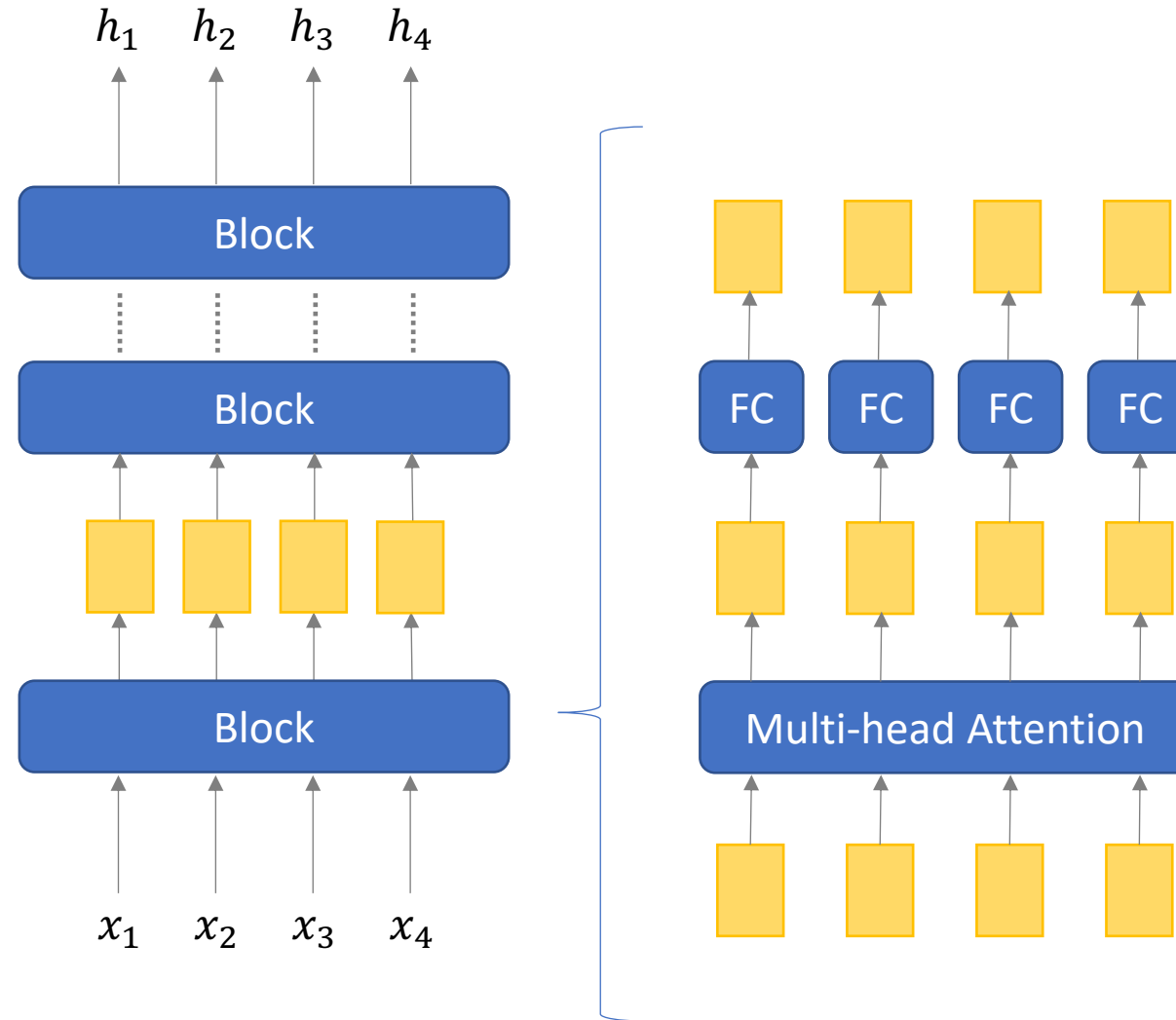
Encoder



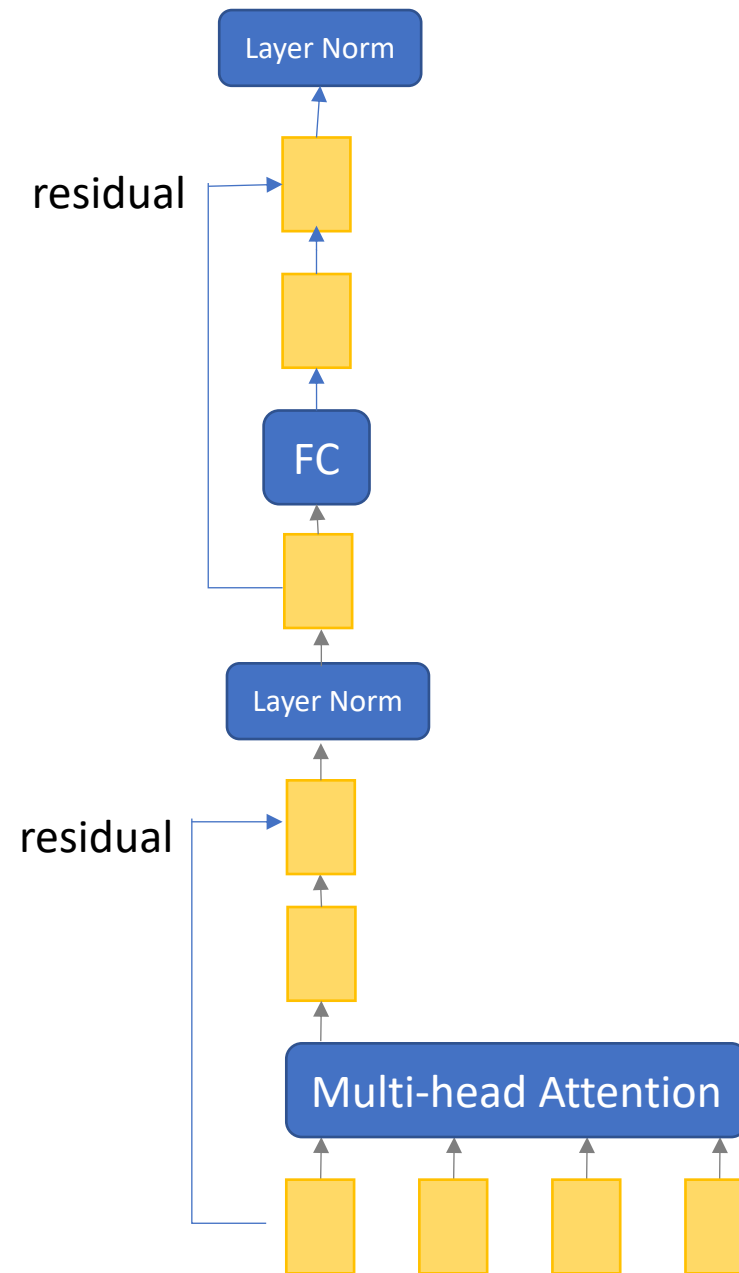
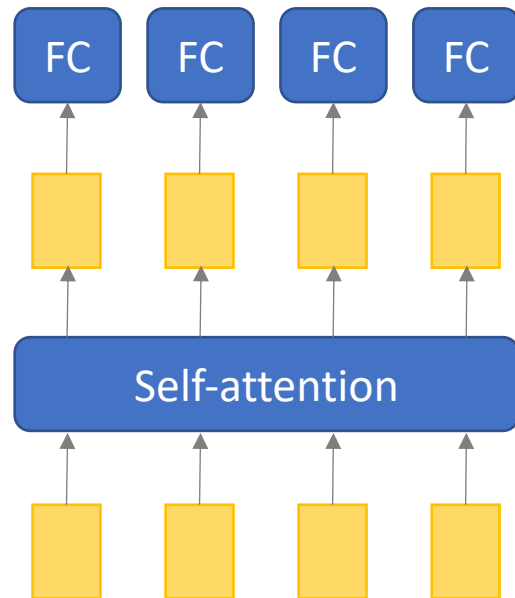
Multi-head attention



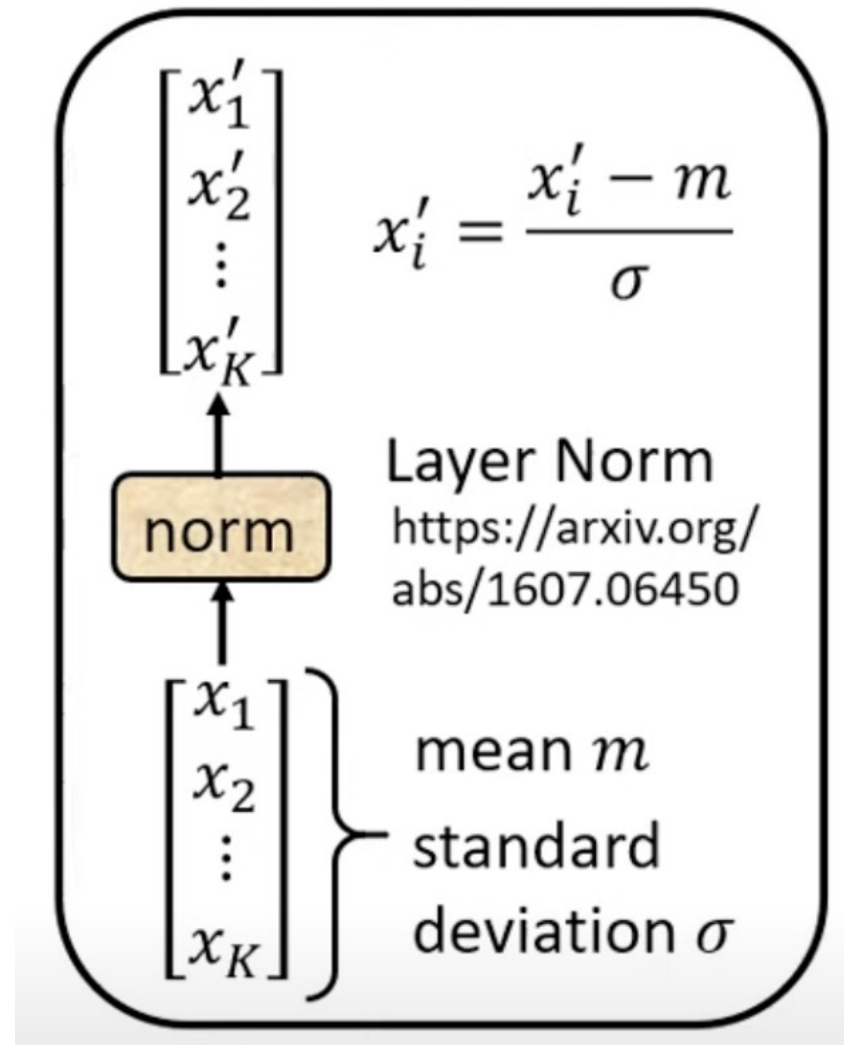
Encoder



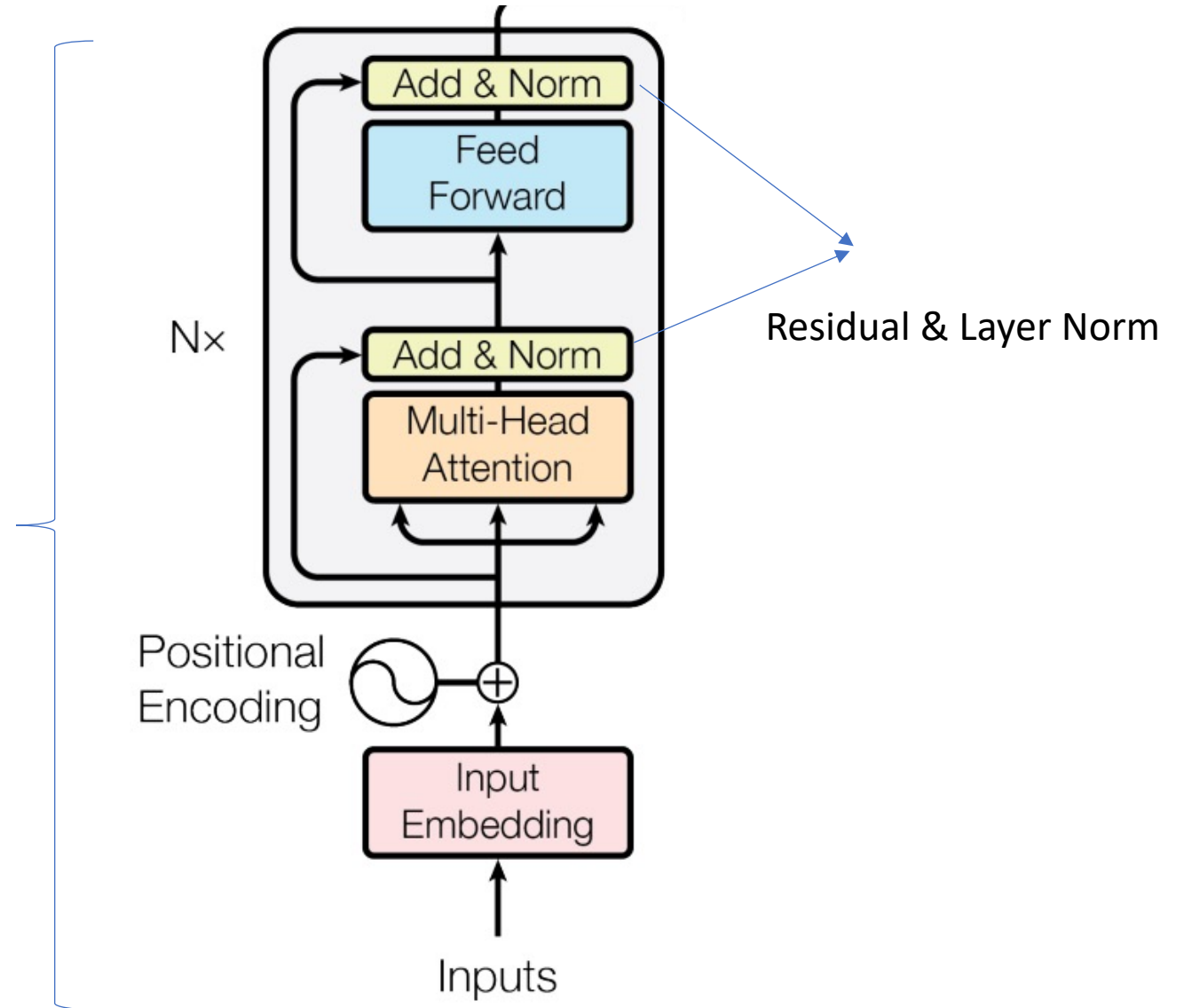
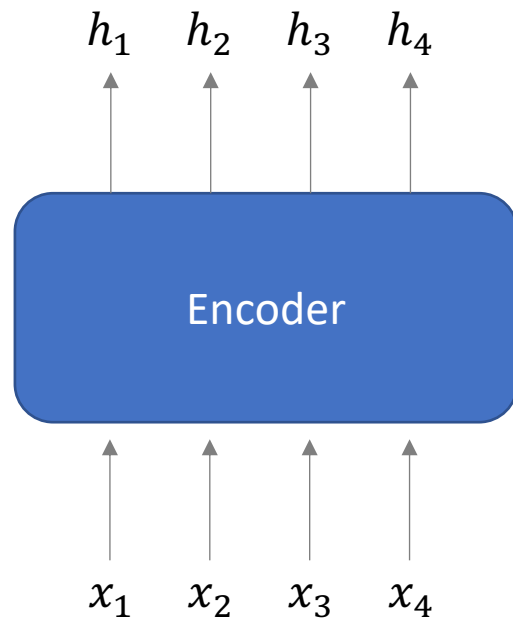
Encoder



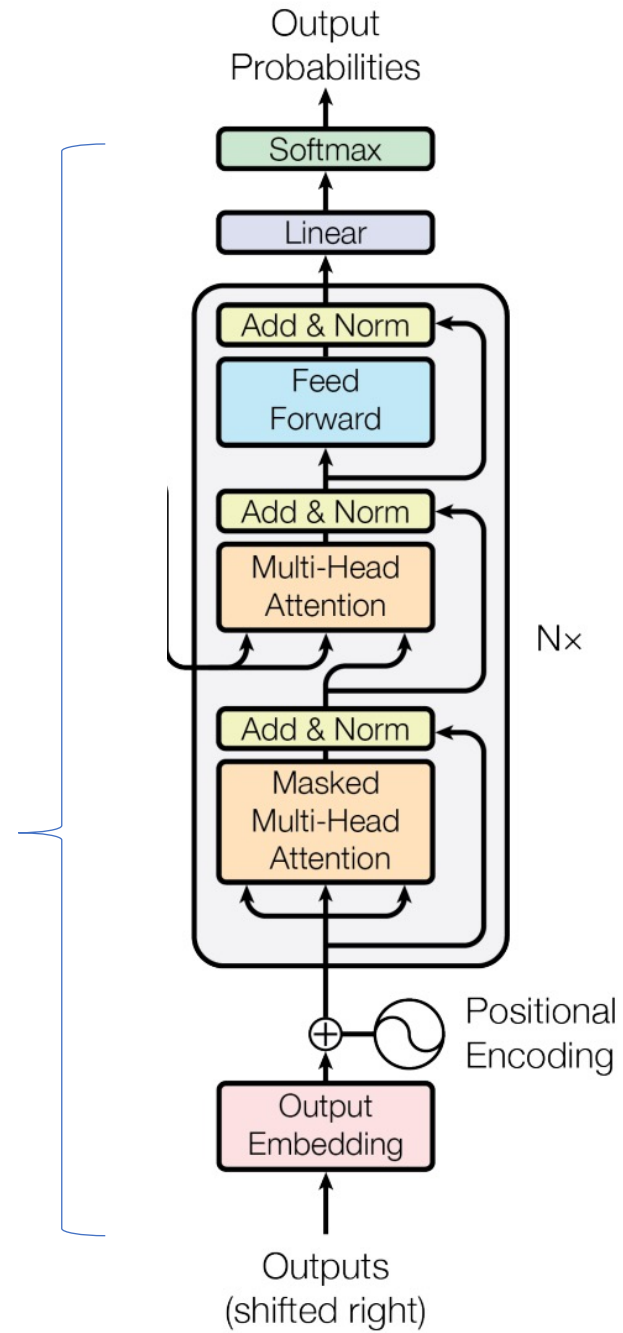
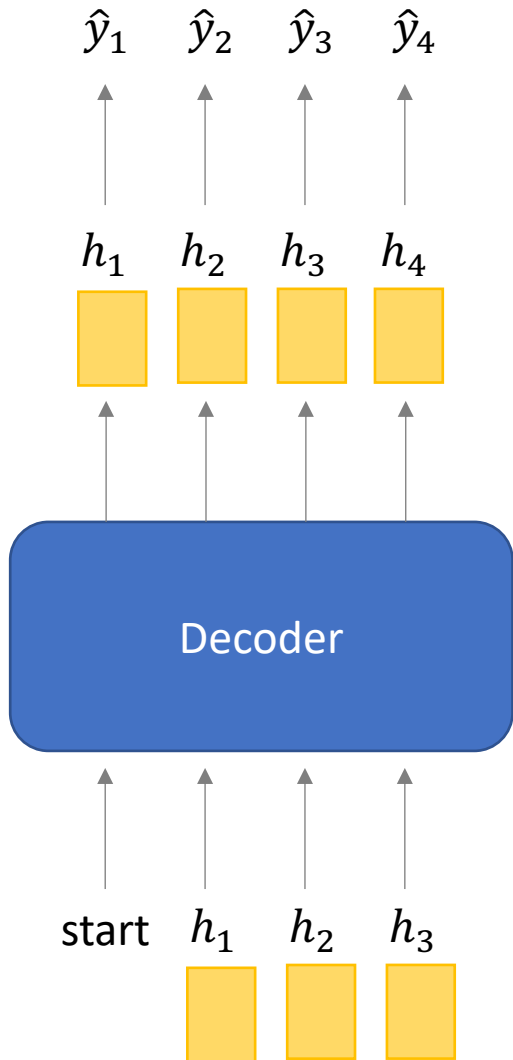
Layer Norm



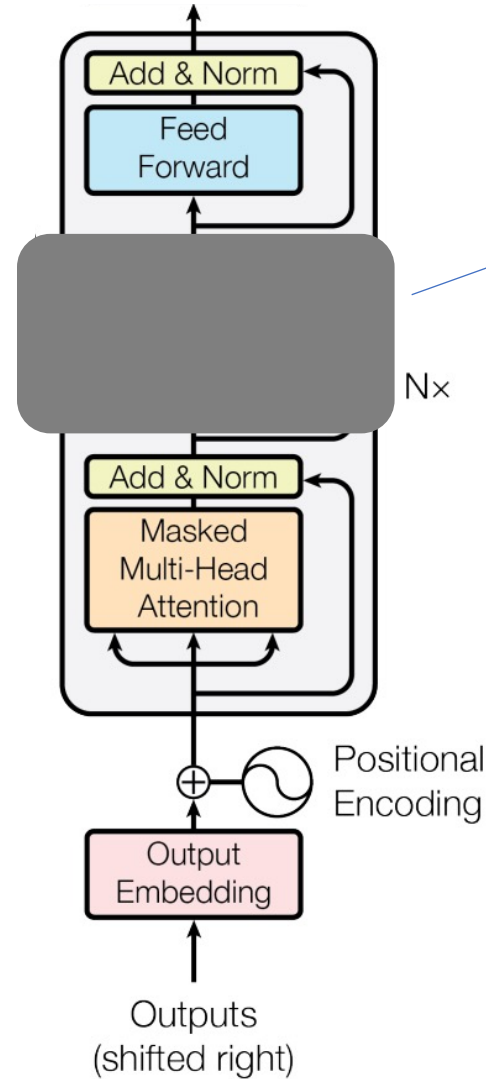
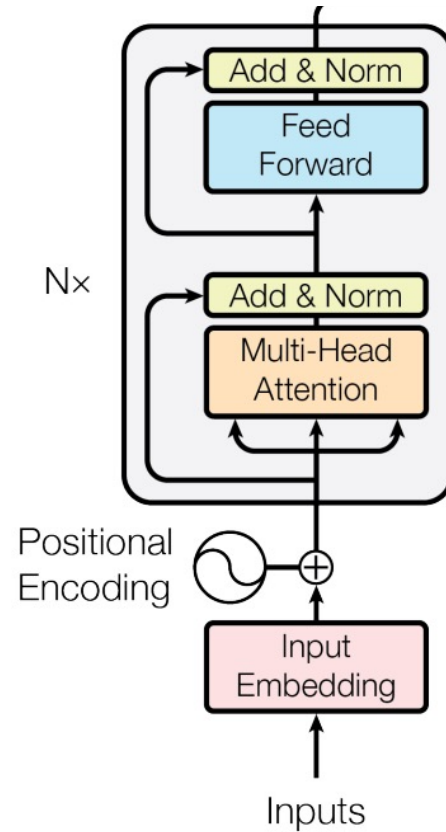
Encoder



Decoder

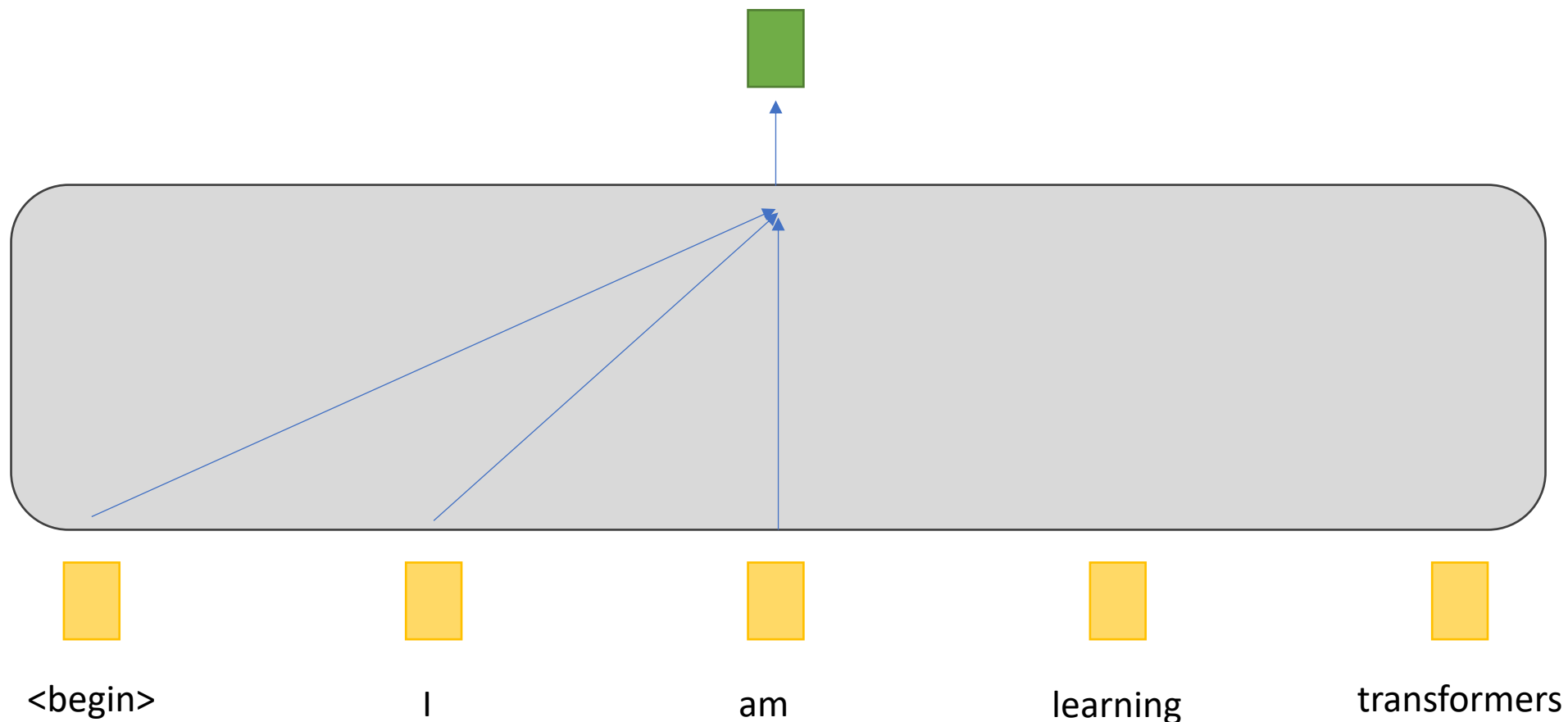


Encoder and Decoder

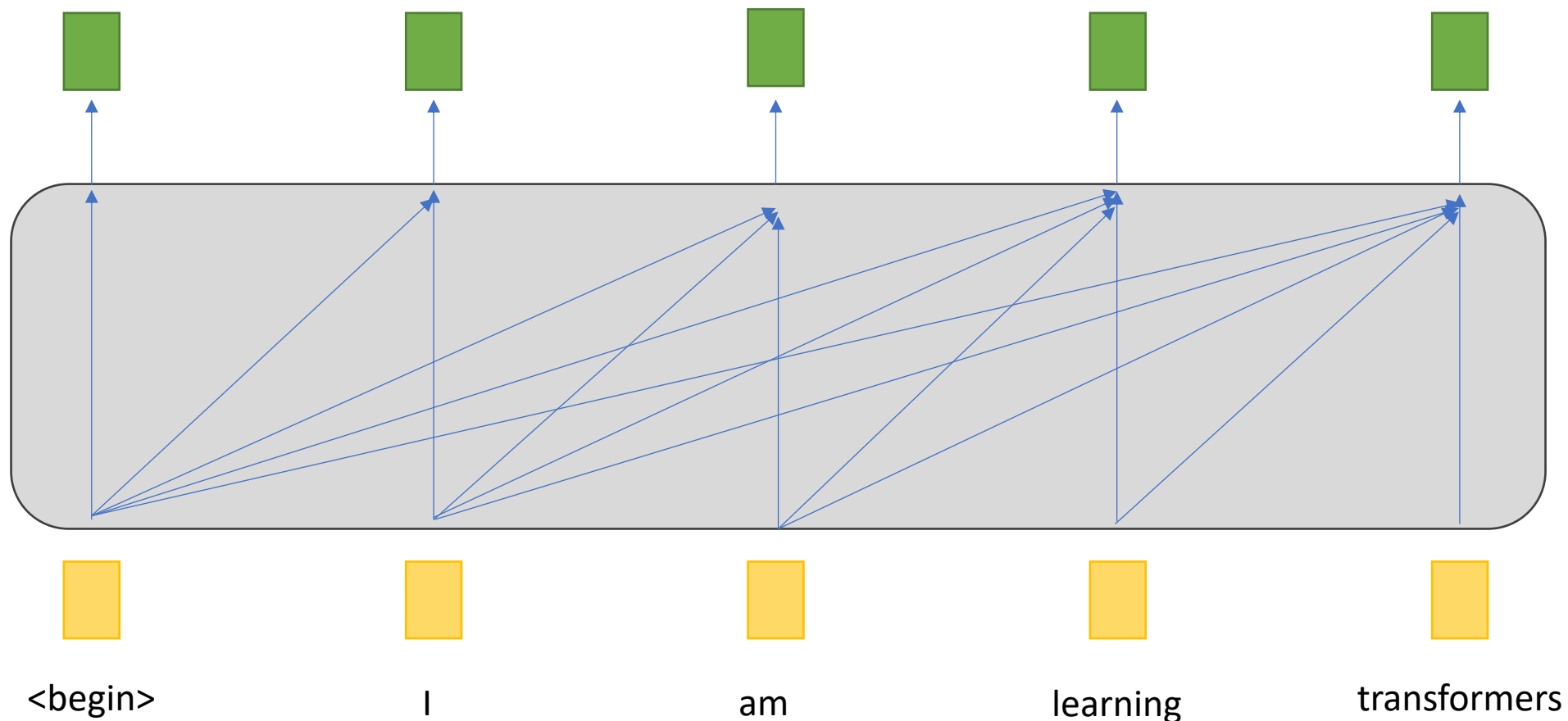


- Let's ignore this for now, will discuss later.
- The rest are very similar to encoder

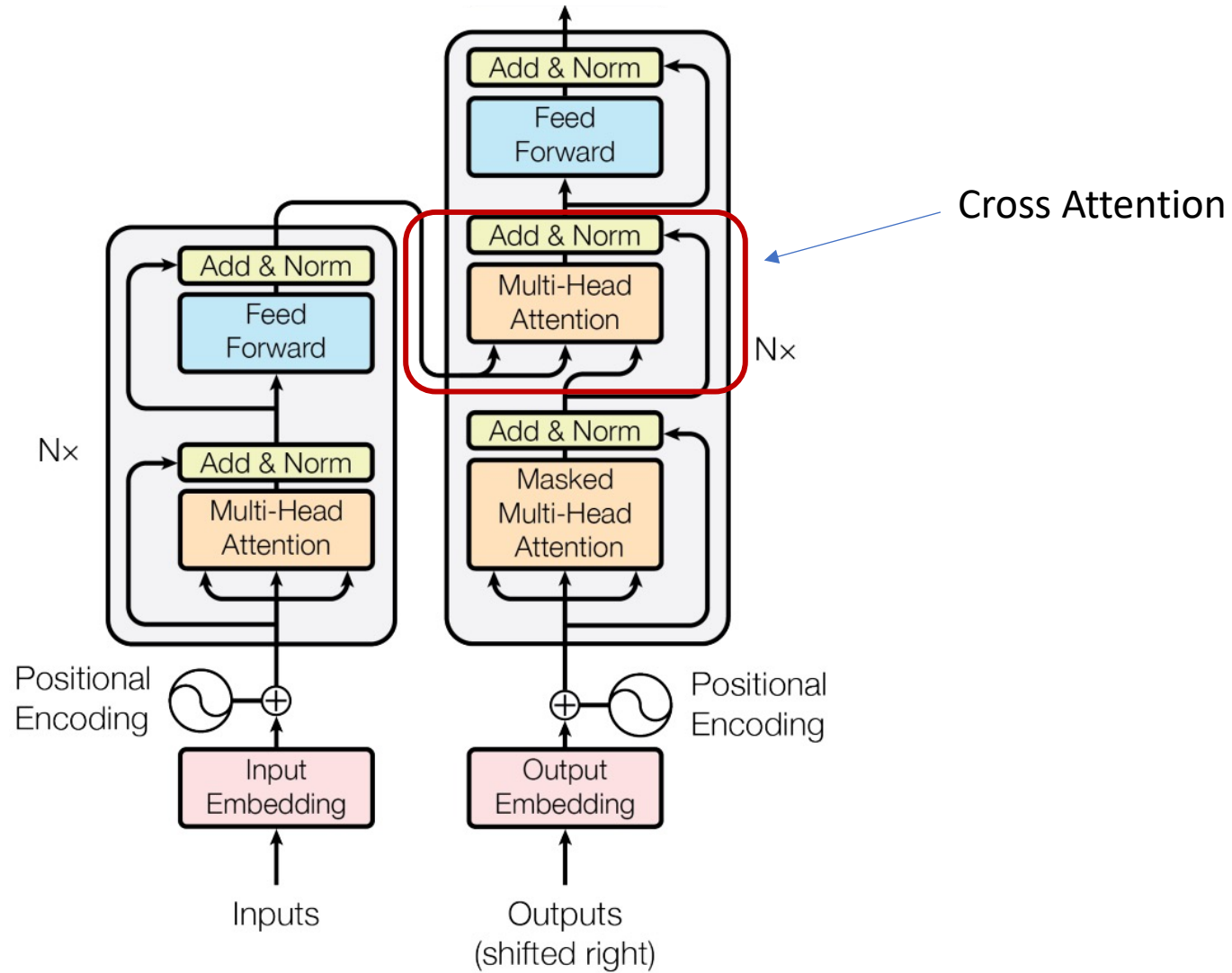
Masked Multi-head Attention



Masked Multi-head Attention



Cross Attention



Cross Attention

