

# Generative Models

Instructor: Alan Ritter

Slides Adapted from Fei-Fei Li & Justin Johnson & Serena Yeung

# Overview

- Unsupervised Learning
- Generative Models
  - PixelRNN and PixelCNN
  - Variational Autoencoders (VAE)
  - Generative Adversarial Networks (GAN)

# Supervised vs Unsupervised Learning

## Supervised Learning

**Data:**  $(x, y)$

$x$  is data,  $y$  is label

**Goal:** Learn a *function* to map  $x \rightarrow y$

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

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→ Cat

Classification

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# 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  
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# Supervised vs Unsupervised Learning

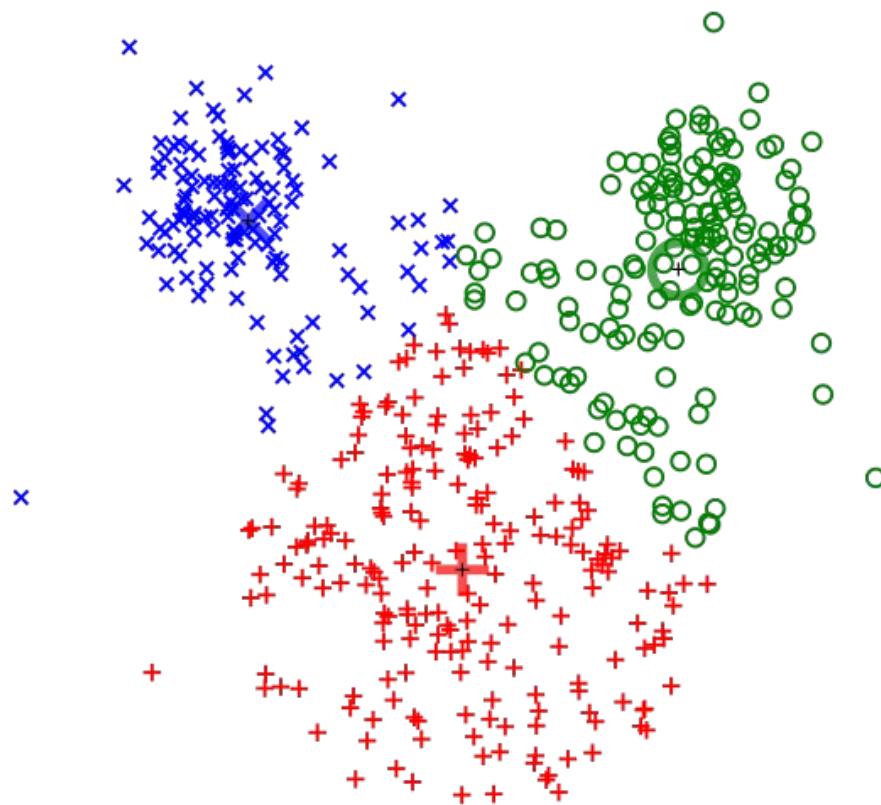
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K-means clustering

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# Supervised vs Unsupervised Learning

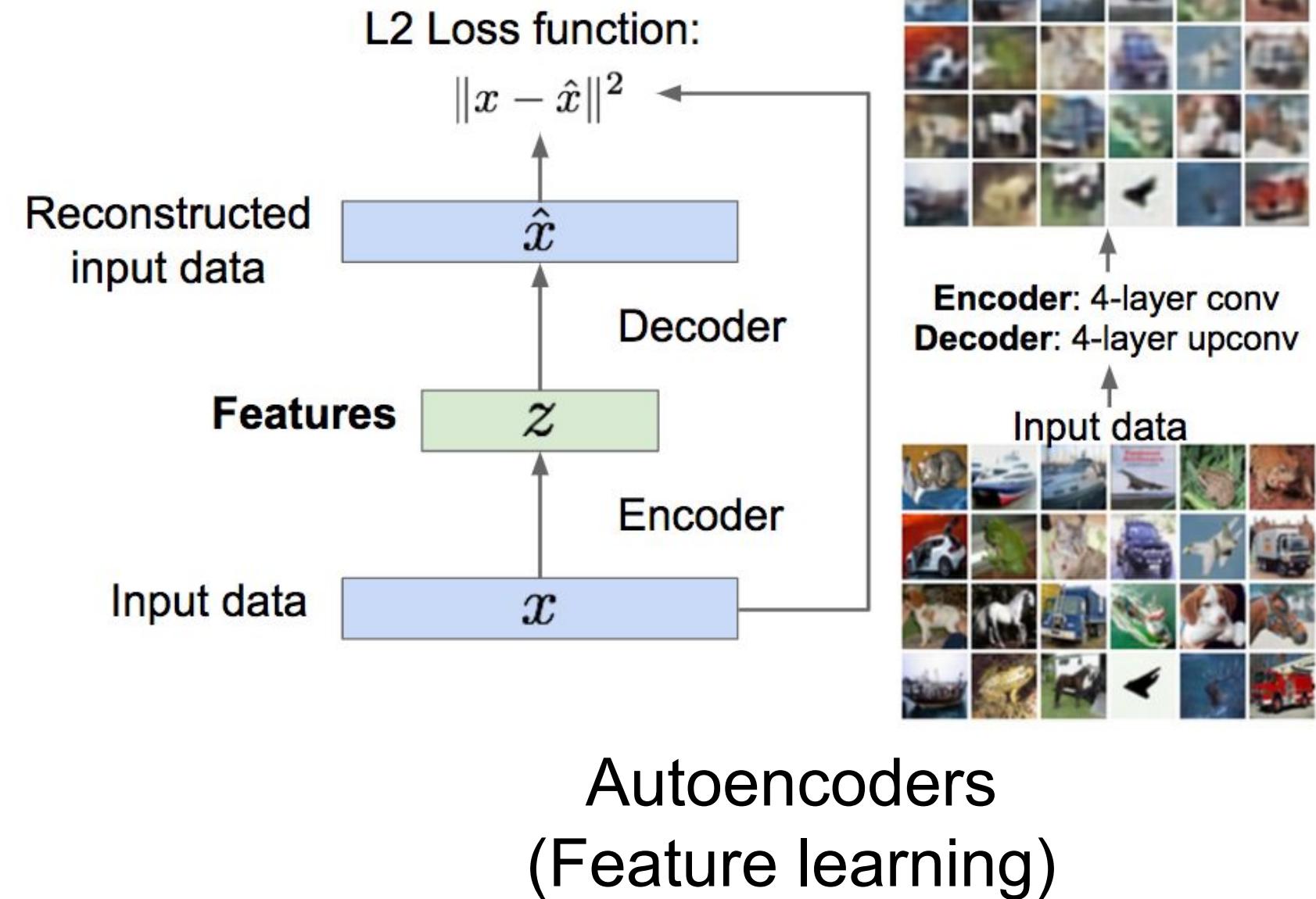
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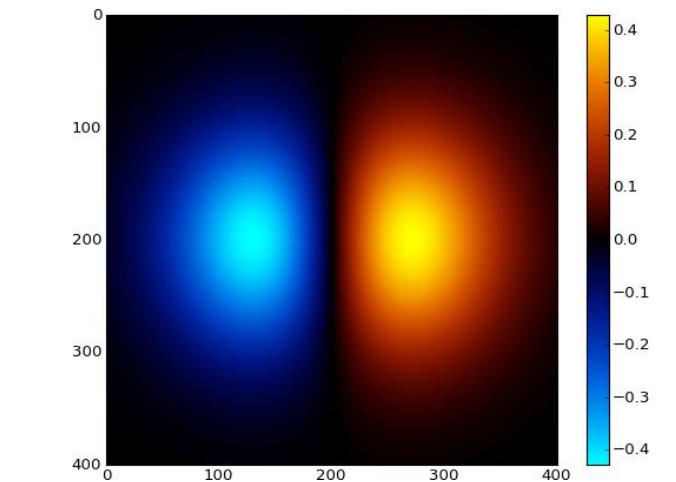
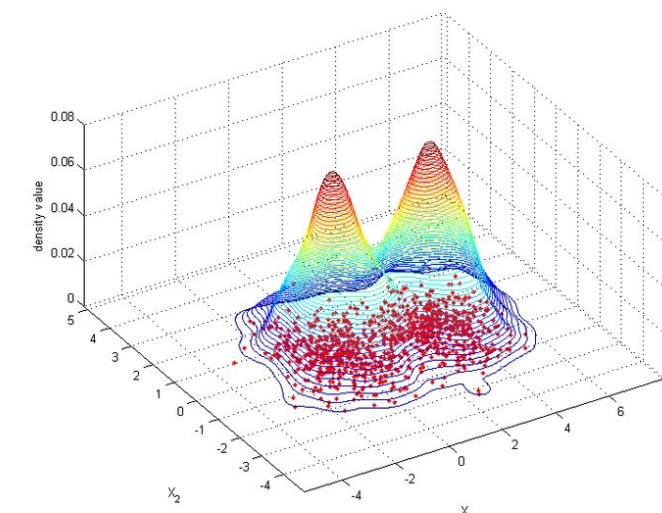
**Goal:** Learn some underlying hidden *structure* of the data

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



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1-d density estimation



2-d density estimation

2-d density images [left](#) and [right](#) are [CC0 public domain](#)

# Supervised vs Unsupervised Learning

## Supervised Learning

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## Unsupervised Learning

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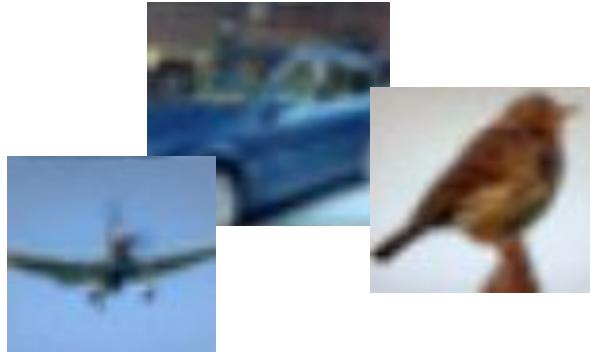
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# Generative Models

Given training data, generate new samples from same distribution



Training data  $\sim p_{\text{data}}(x)$



Generated samples  $\sim p_{\text{model}}(x)$

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

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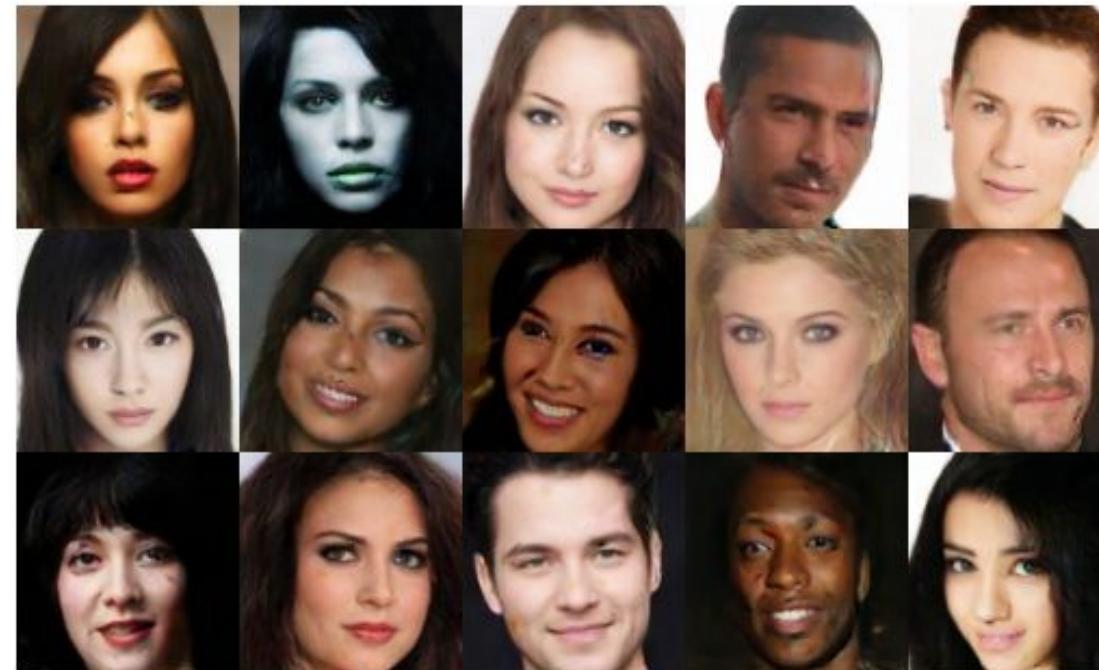
Addresses density estimation, a core problem in unsupervised learning

**Several flavors:**

- Explicit density estimation: explicitly define and solve for  $p_{\text{model}}(x)$
- Implicit density estimation: learn model that can sample from  $p_{\text{model}}(x)$  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

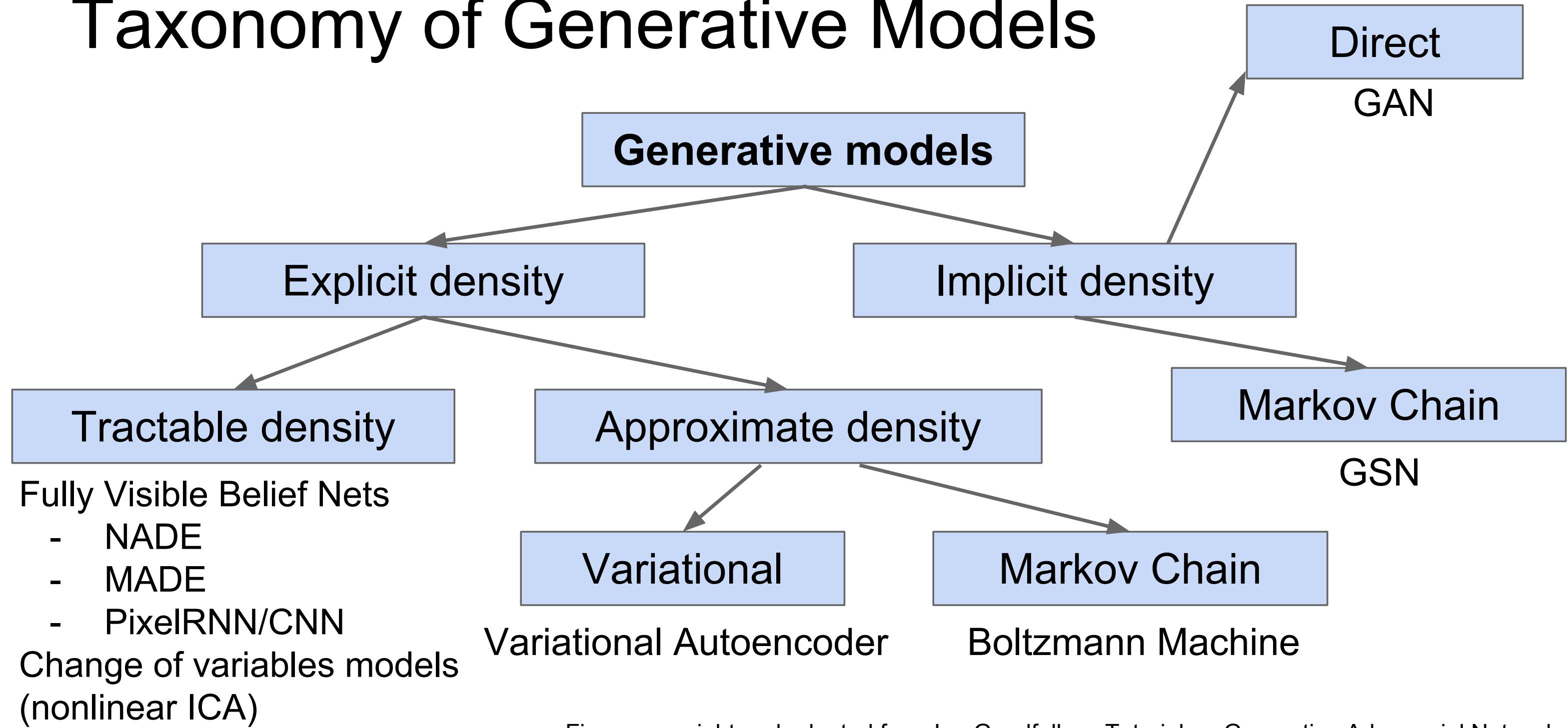


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# Taxonomy of Generative Models

Today: discuss 3 most popular types of generative models today

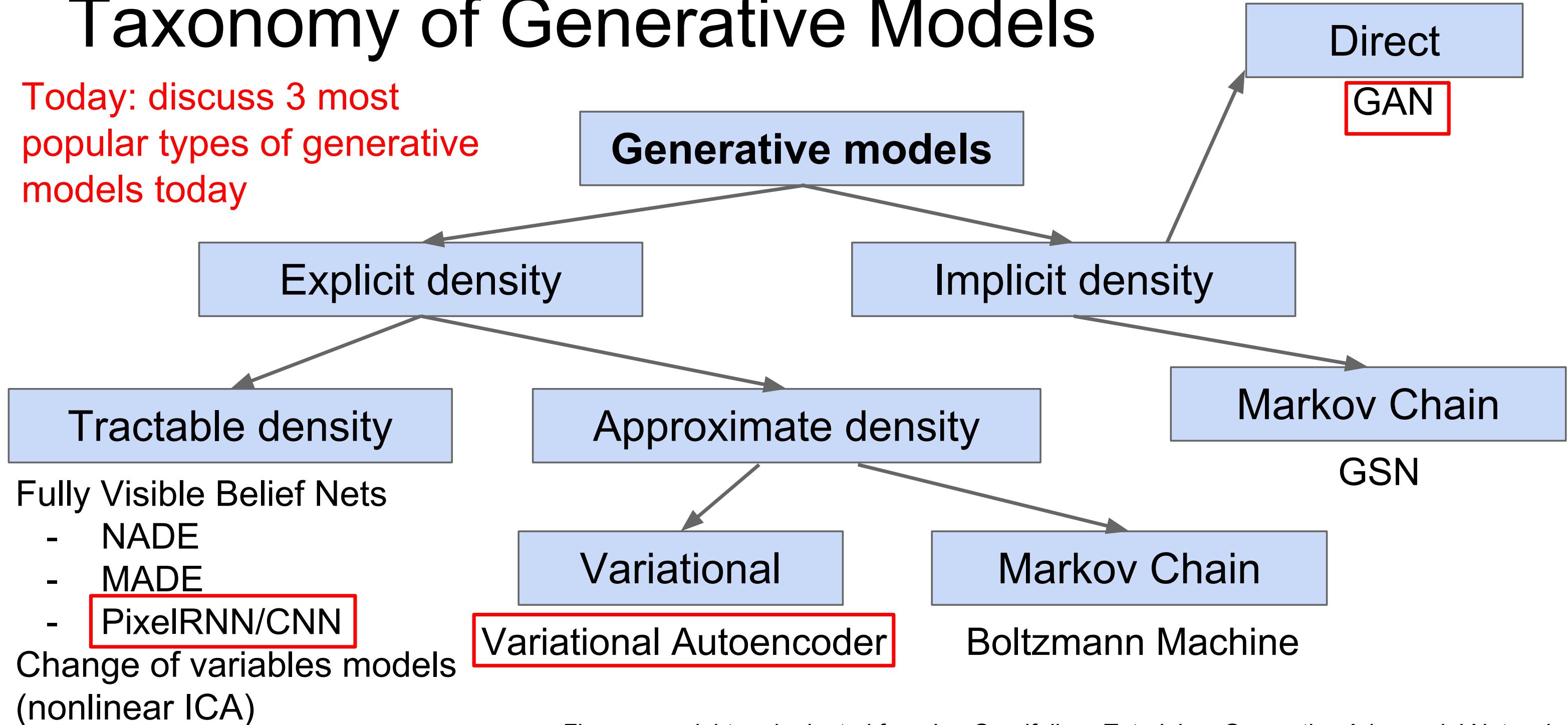


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# PixelRNN and PixelCNN

# Fully visible belief network

# Explicit density model

Use chain rule to decompose likelihood of an image  $x$  into product of 1-d distributions:

Then maximize likelihood of training data

# Fully visible belief network

# Explicit density model

Use chain rule to decompose likelihood of an image  $x$  into product of 1-d distributions:

$$p(x) = \prod_{i=1}^n p(x_i | x_1, \dots, x_{i-1})$$

## Likelihood of image x

## Probability of i'th pixel value given all previous pixels

Complex distribution over pixel values => Express using a neural network!

Then maximize likelihood of training data

# Fully visible belief network

# Explicit density model

Use chain rule to decompose likelihood of an image  $x$  into product of 1-d distributions:

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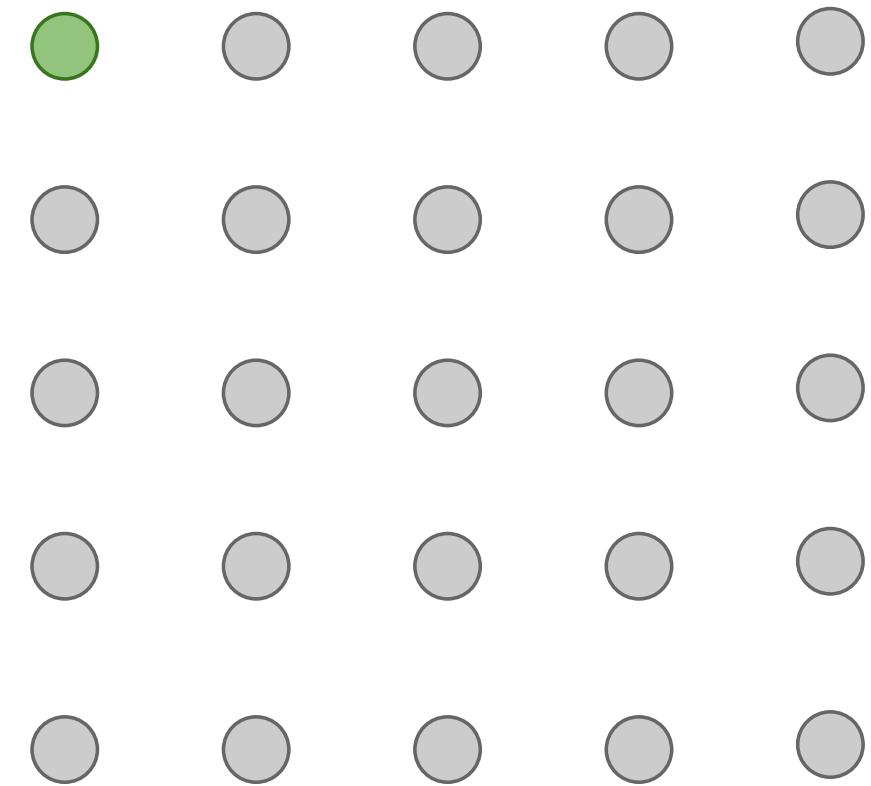
Will need to define ordering of “previous pixels”

Complex distribution over pixel values => Express using a neural network!

# PixelRNN

[van der Oord et al. 2016]

Generate image pixels starting from corner



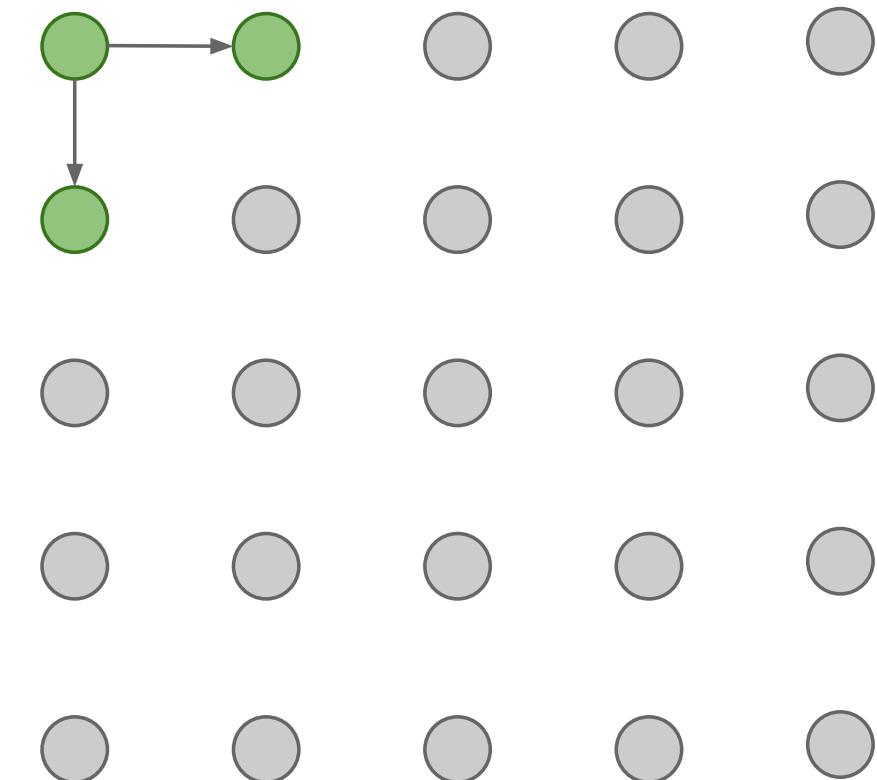
Dependency on previous pixels modeled  
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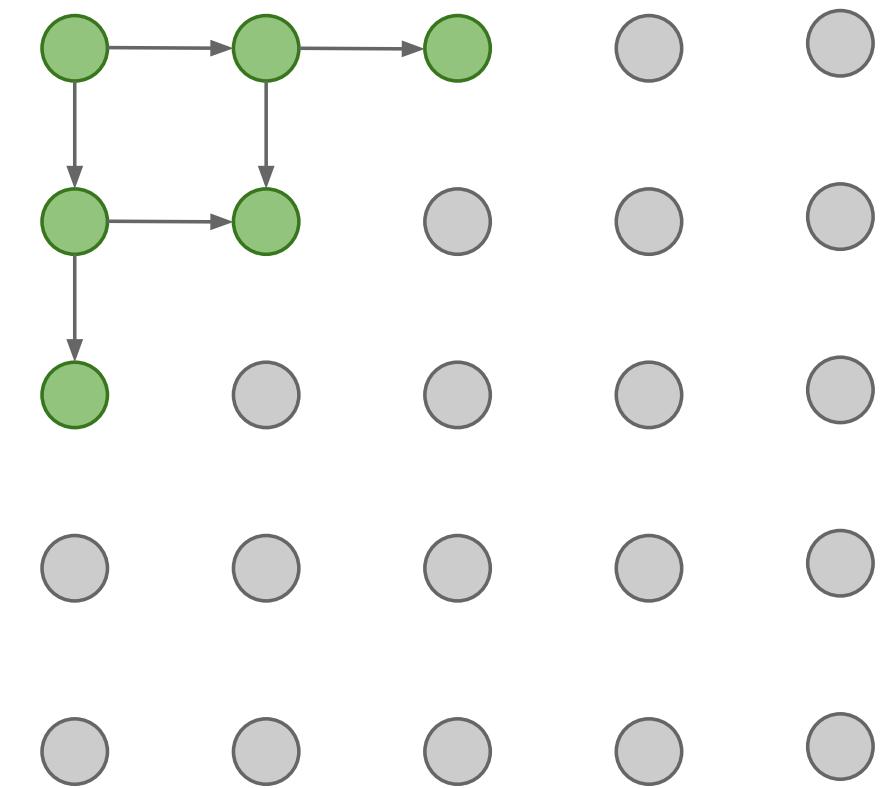


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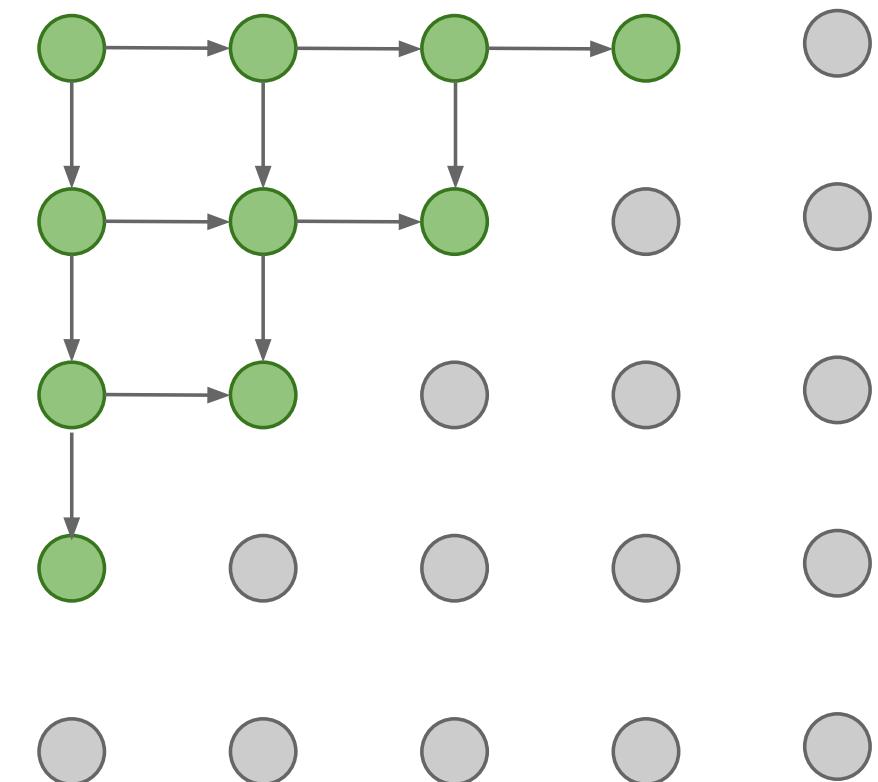
# PixelRNN

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Drawback: sequential generation is slow!



# PixelCNN

[van der Oord et al. 2016]

Still generate image pixels starting from corner

Dependency on previous pixels now modeled using a CNN over context region

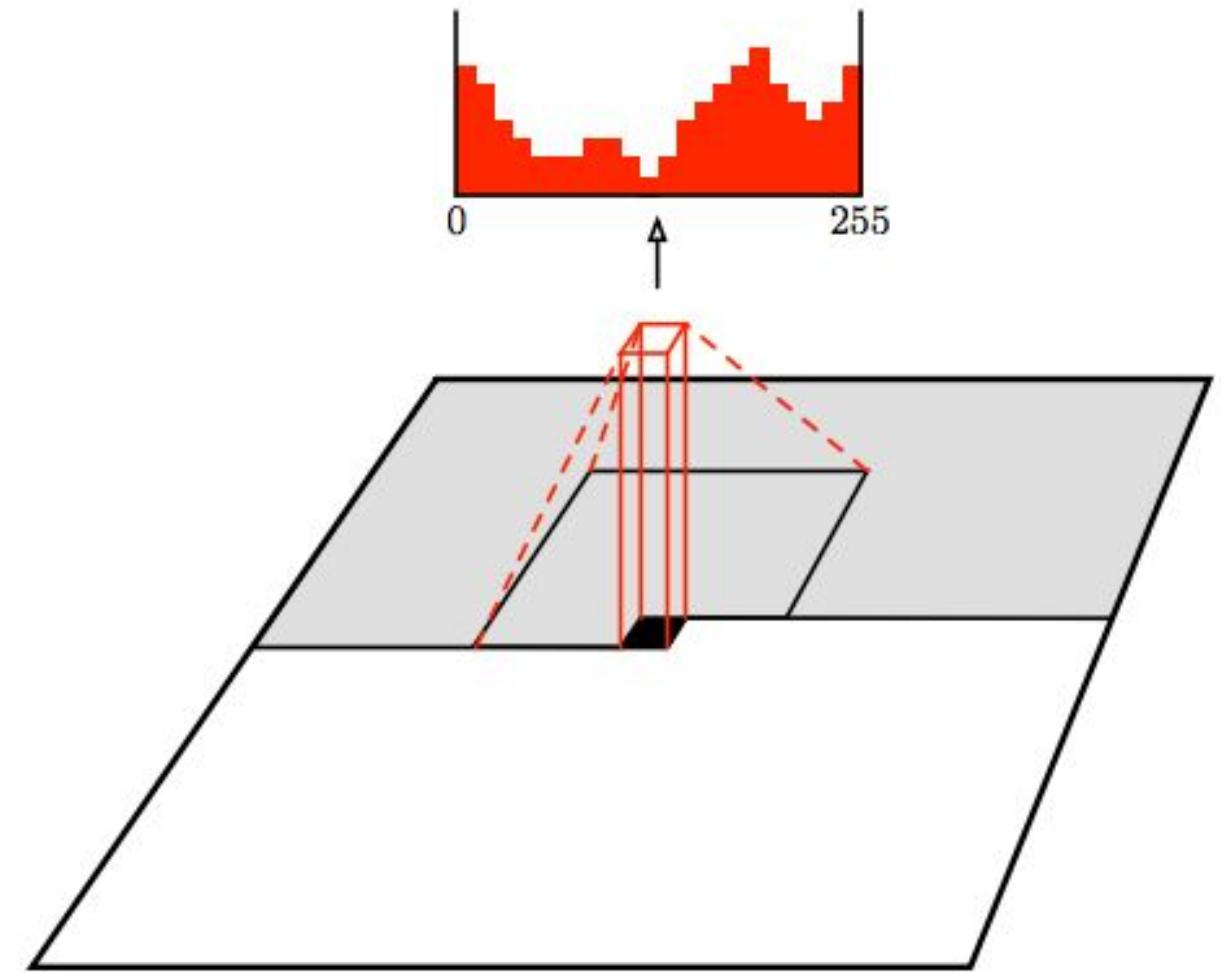


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# PixelCNN

[van der Oord et al. 2016]

Still generate image pixels starting from corner

Dependency on previous pixels now modeled using a CNN over context region

Training: maximize likelihood of training images

$$p(x) = \prod_{i=1}^n p(x_i|x_1, \dots, x_{i-1})$$

Softmax loss at each pixel

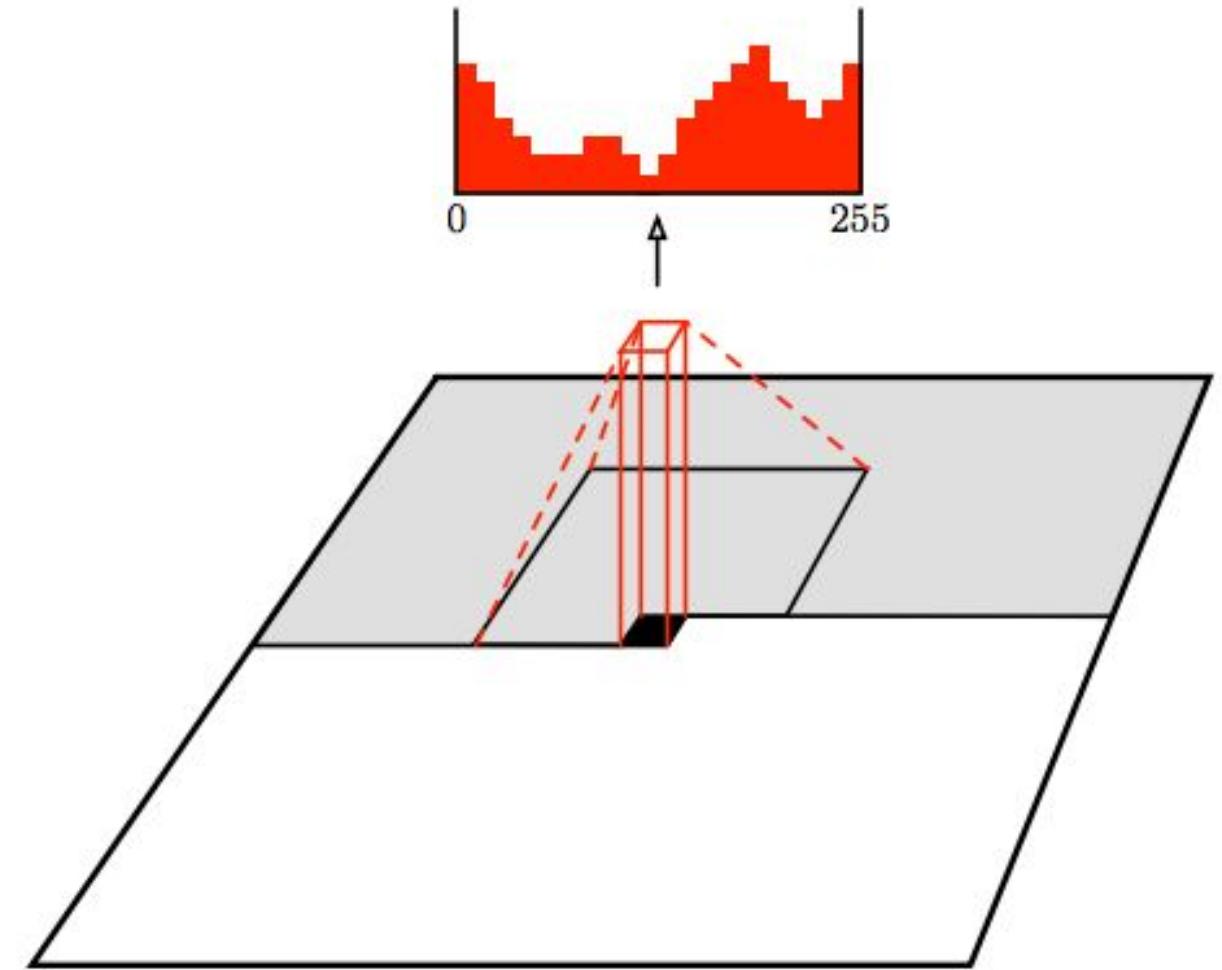


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# PixelCNN

[van der Oord et al. 2016]

Still generate image pixels starting from corner

Dependency on previous pixels now modeled using a CNN over context region

Training is faster than PixelRNN  
(can parallelize convolutions since context region values known from training images)

Generation must still proceed sequentially  
=> still slow

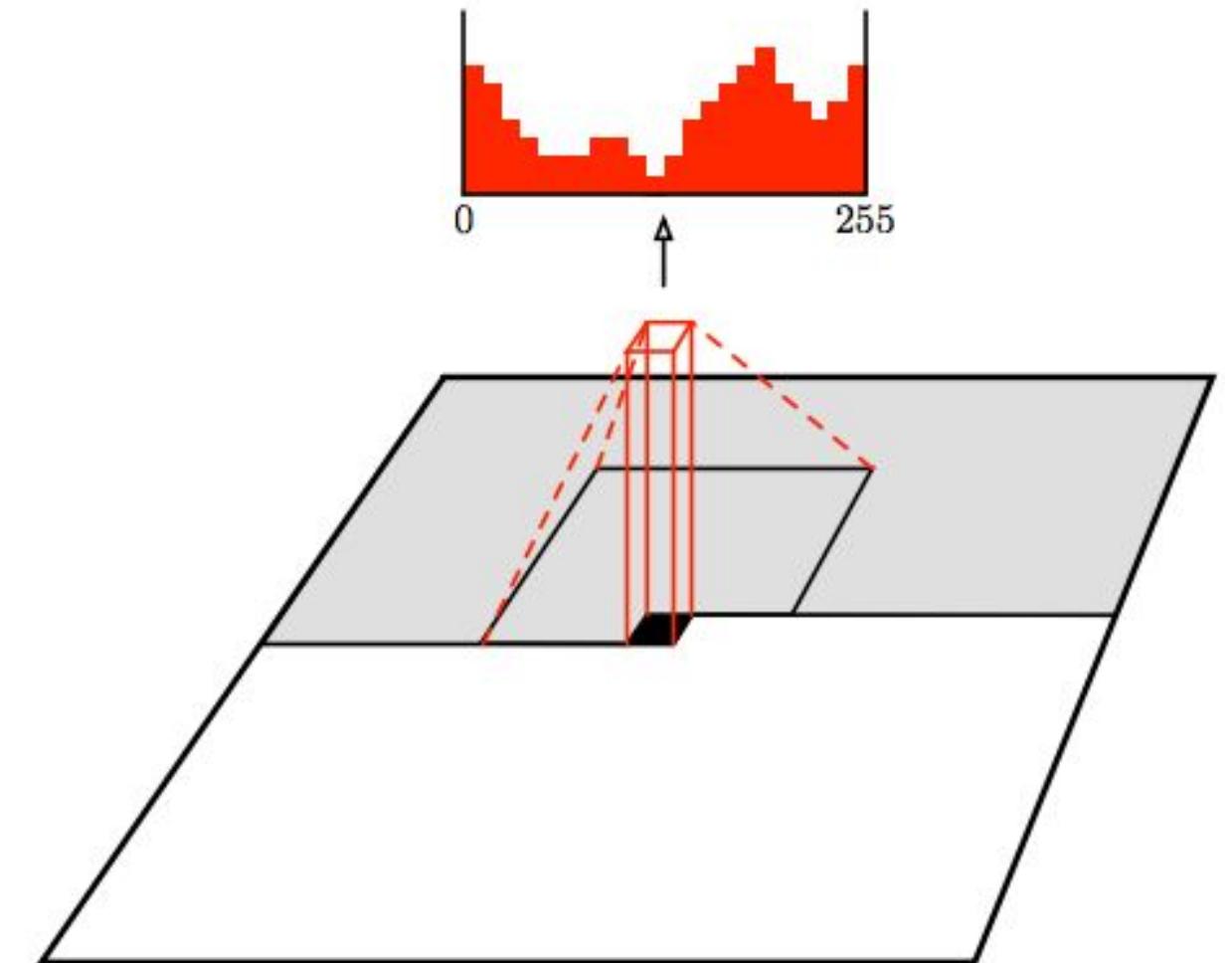
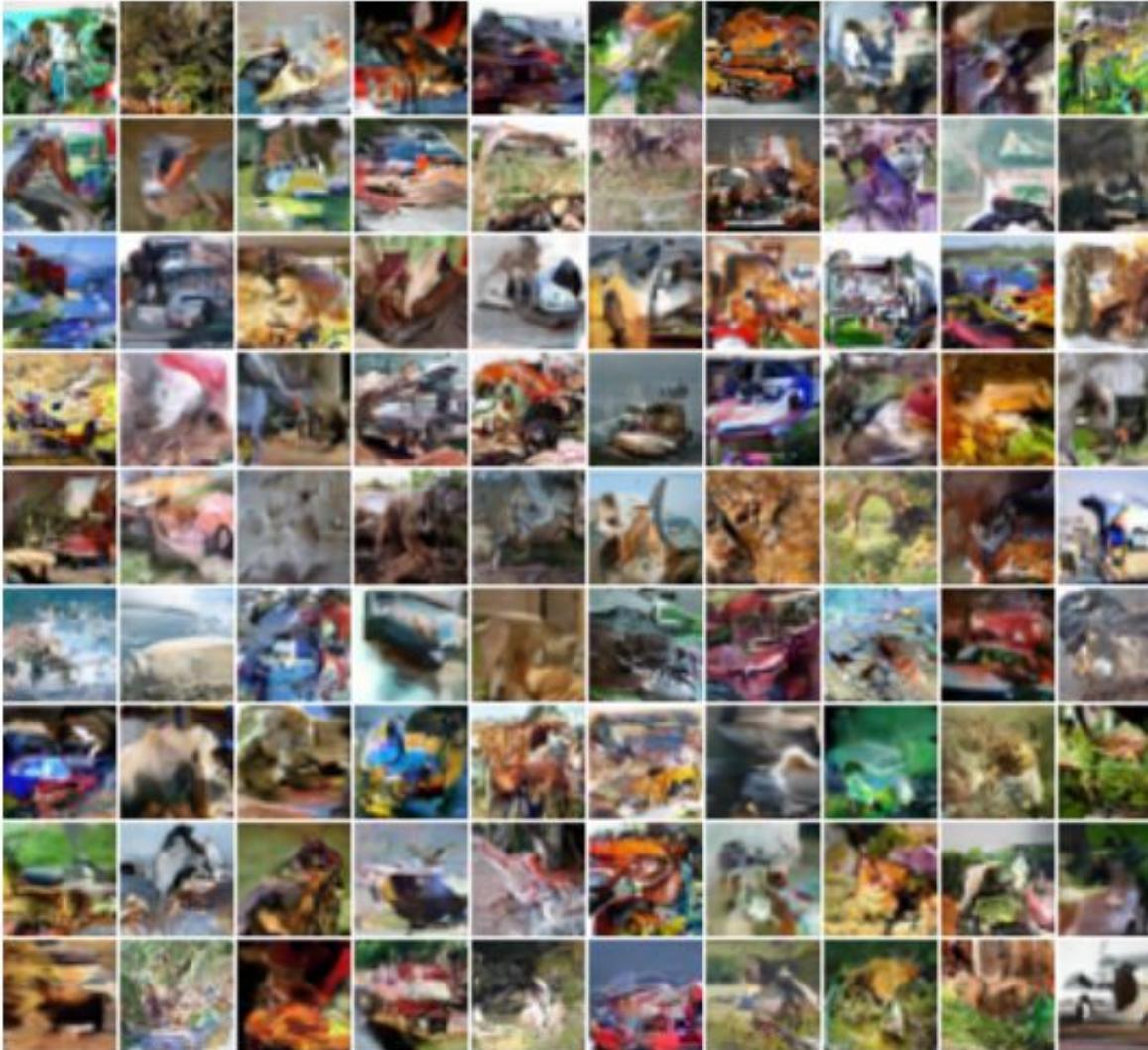
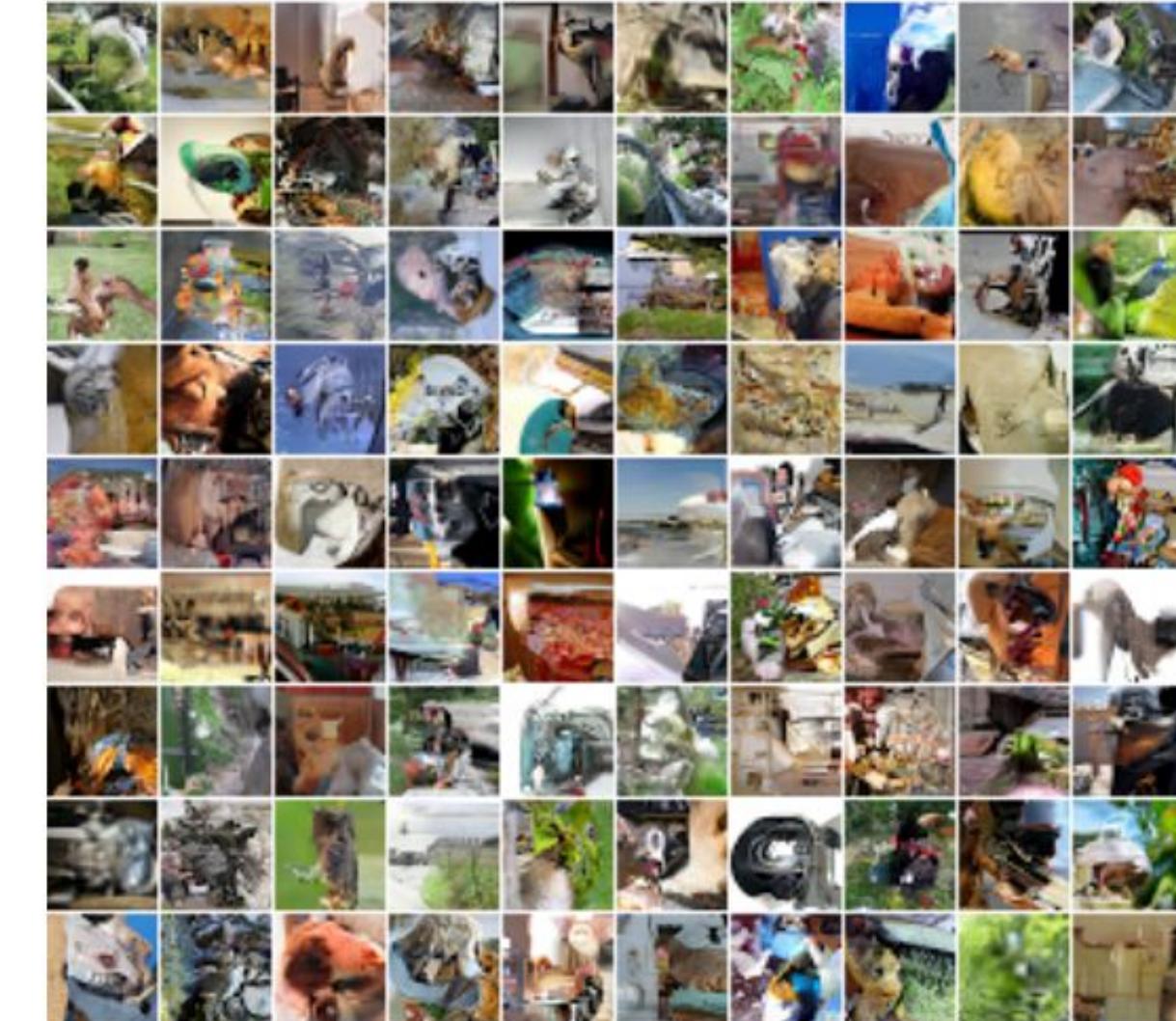


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# Generation Samples



32x32 CIFAR-10



32x32 ImageNet

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# PixelRNN and PixelCNN

## Pros:

- Can explicitly compute likelihood  $p(x)$
- Explicit likelihood of training data gives good evaluation metric
- Good samples

## Con:

- Sequential generation => slow

## Improving PixelCNN performance

- Gated convolutional layers
- Short-cut connections
- Discretized logistic loss
- Multi-scale
- Training tricks
- Etc...

## See

- Van der Oord et al. NIPS 2016
- Salimans et al. 2017  
(PixelCNN++)

# Variational Autoencoders (VAE)

# So far...

PixelCNNs define tractable density function, optimize likelihood of training data:

$$p_{\theta}(x) = \prod_{i=1}^n p_{\theta}(x_i|x_1, \dots, x_{i-1})$$

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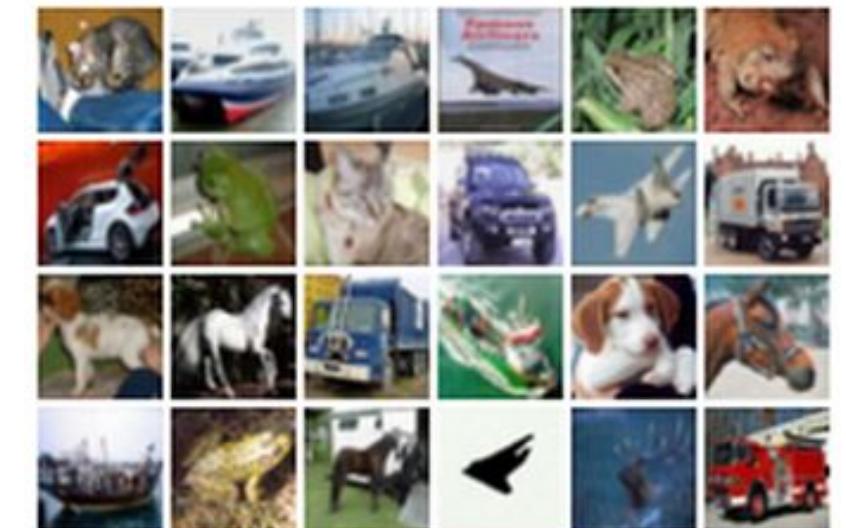
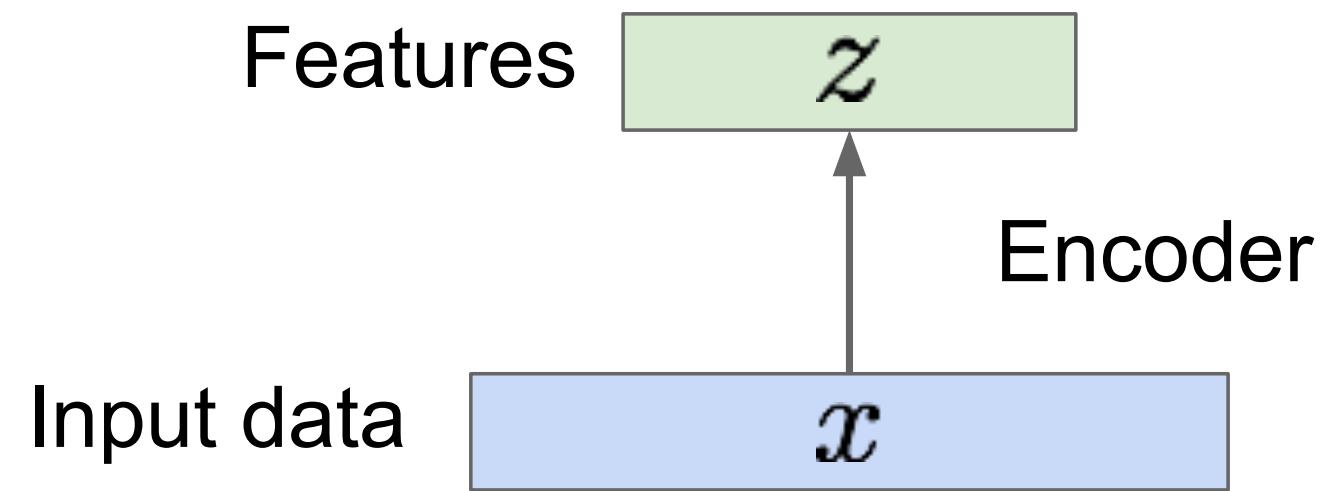
VAEs define intractable density function with latent  $\mathbf{z}$ :

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

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

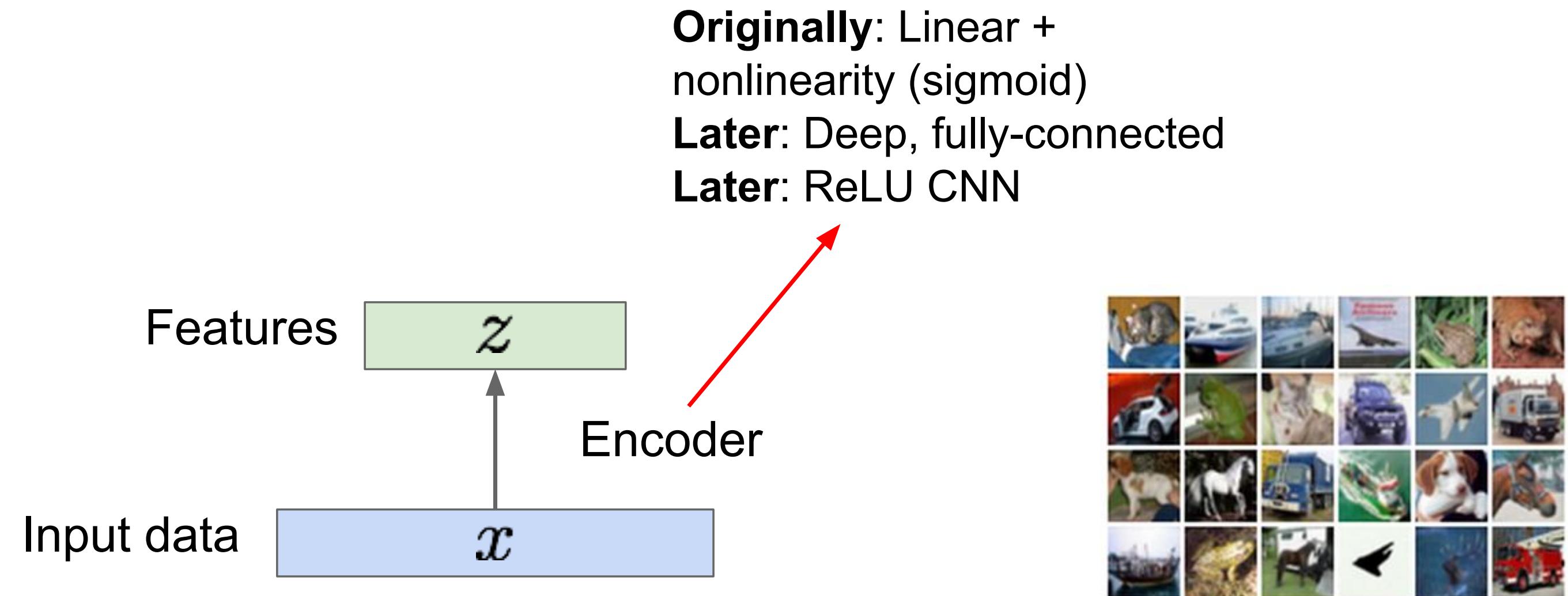
# Some background first: Autoencoders

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



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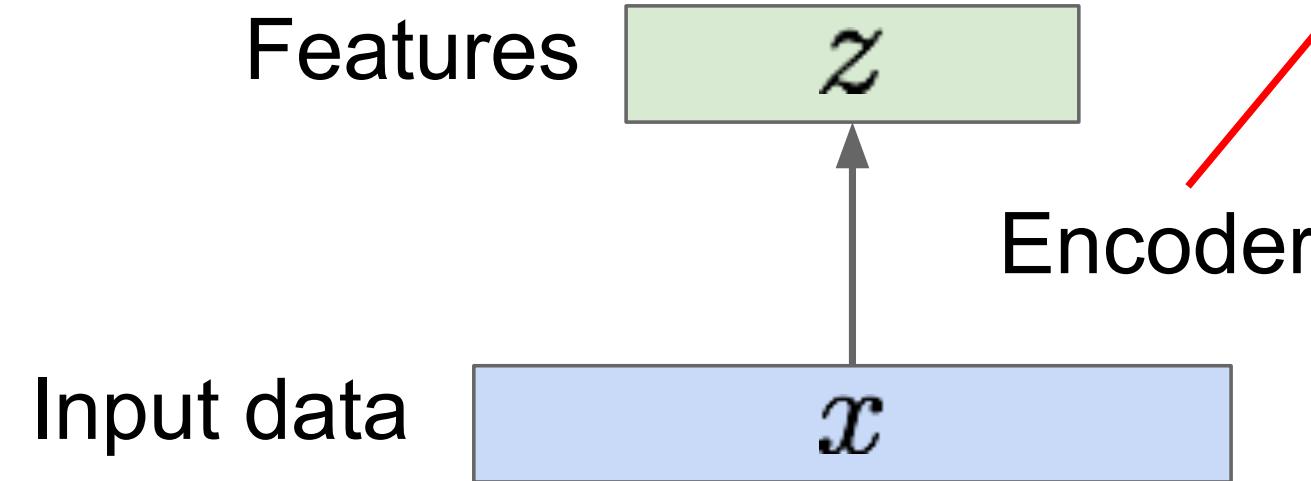


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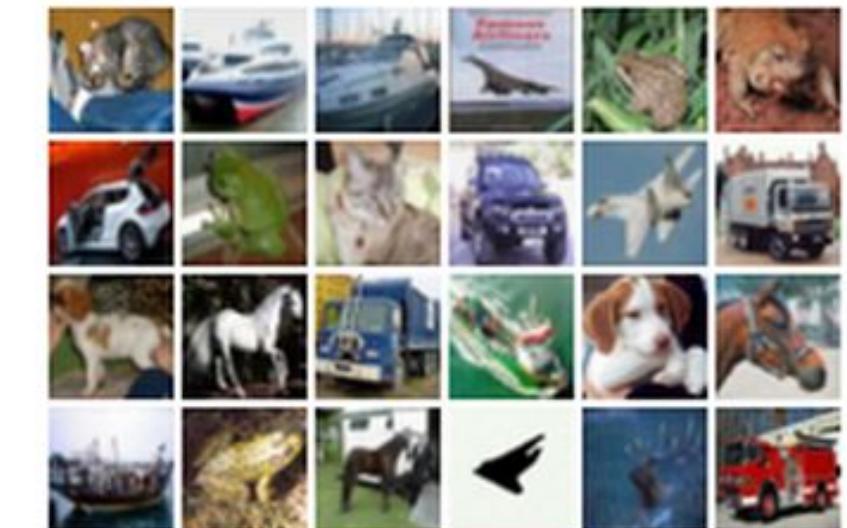
Unsupervised approach for learning a lower-dimensional feature representation from unlabeled training data

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

Q: Why dimensionality reduction?



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



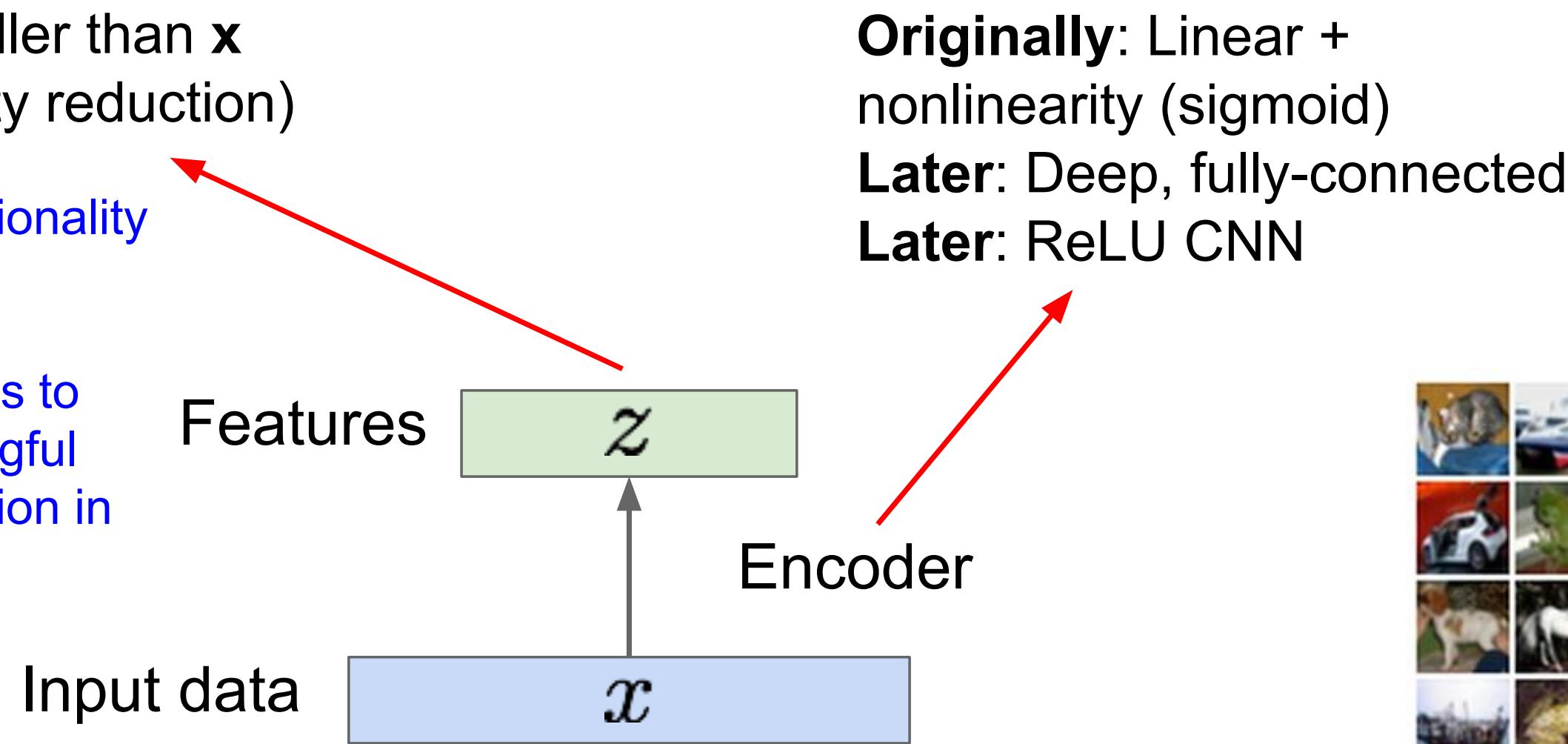
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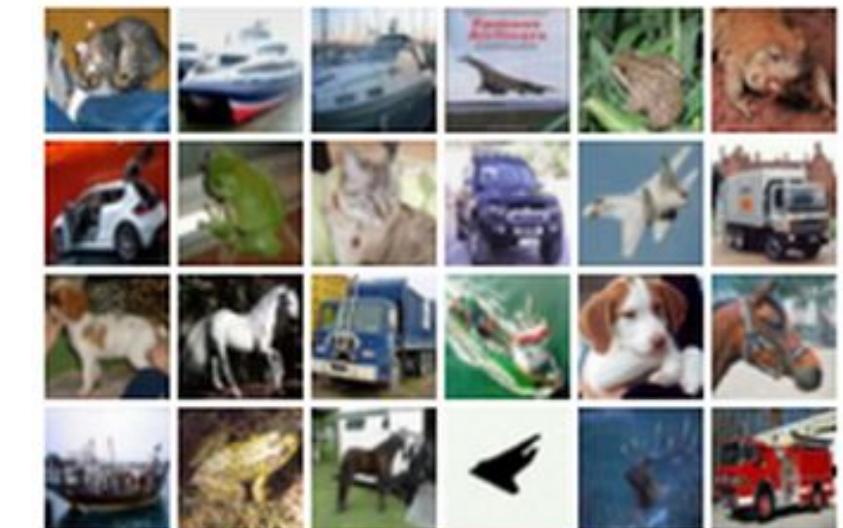
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Q: Why dimensionality reduction?

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

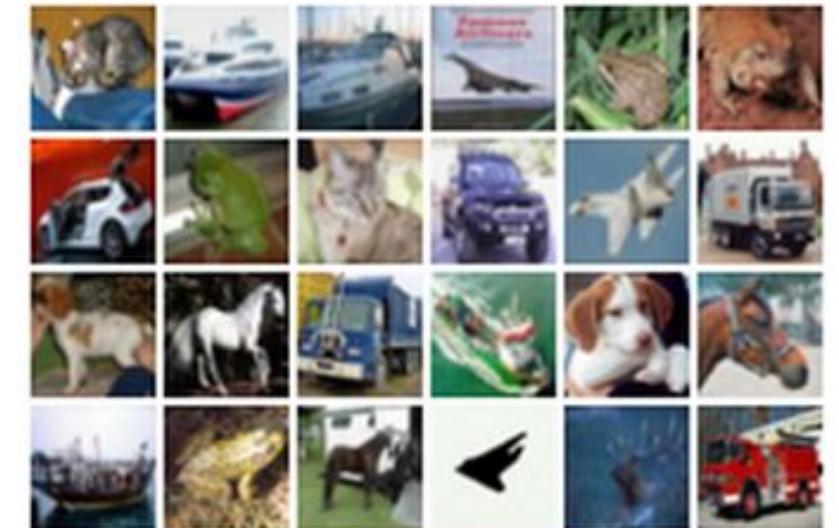
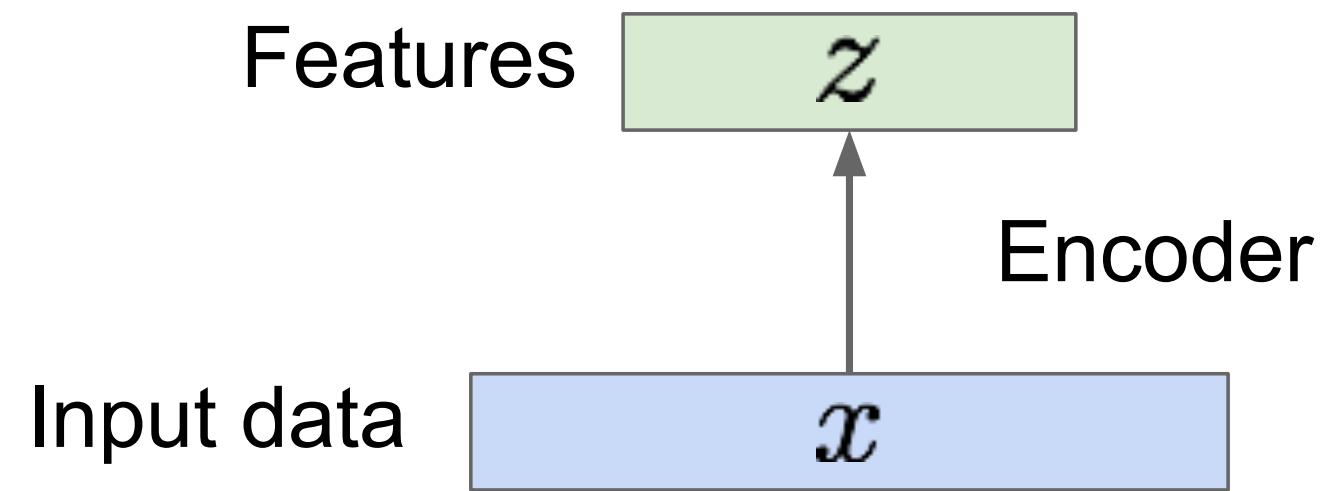


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# How to learn this feature representation?

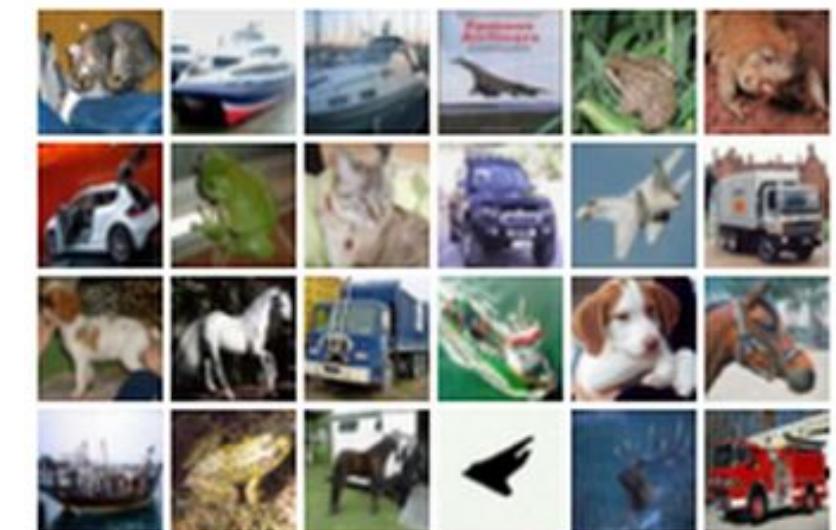
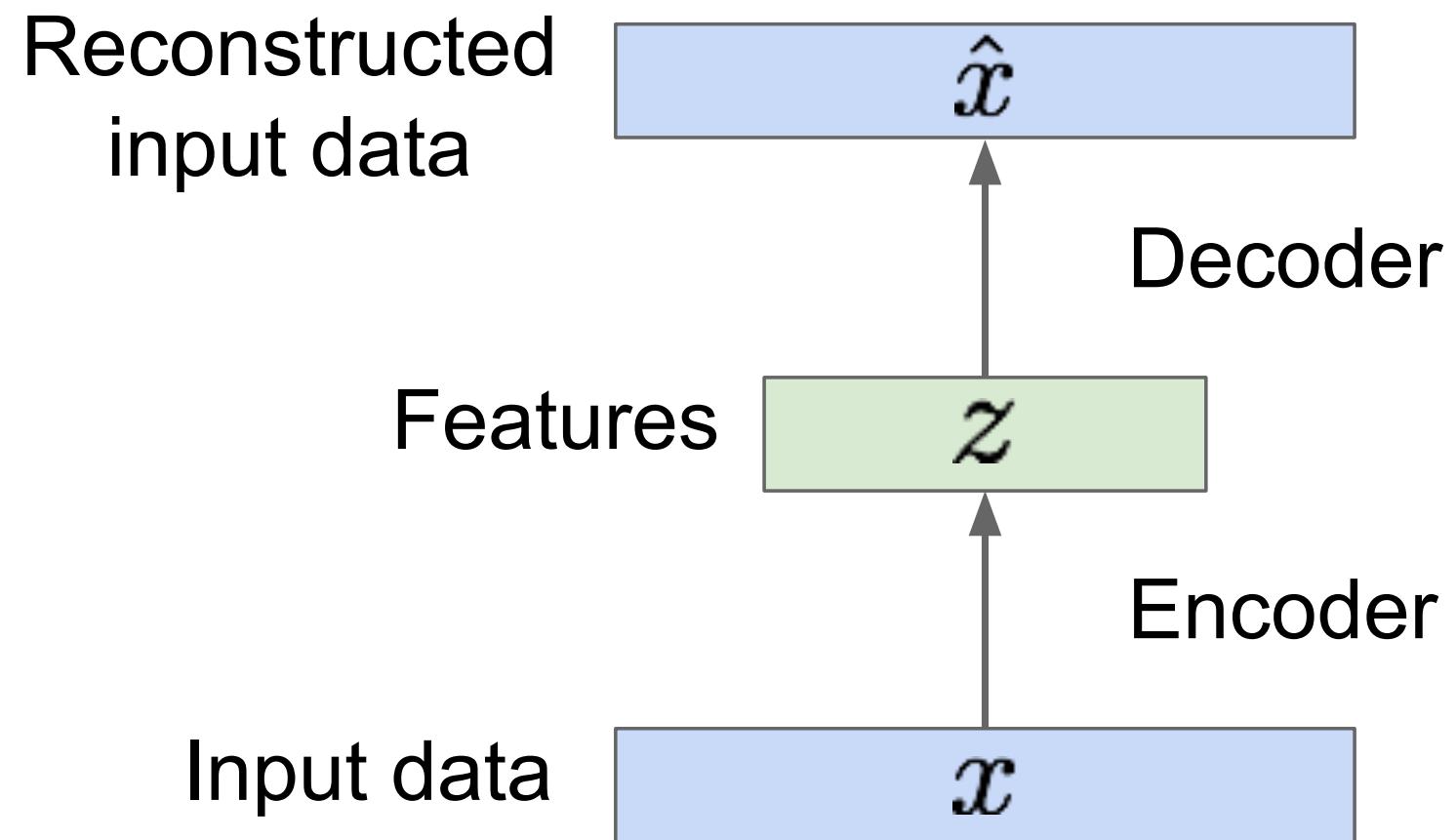


# Some background first: Autoencoders

How to learn this feature representation?

Train such that features can be used to reconstruct original data

“Autoencoding” - encoding itself

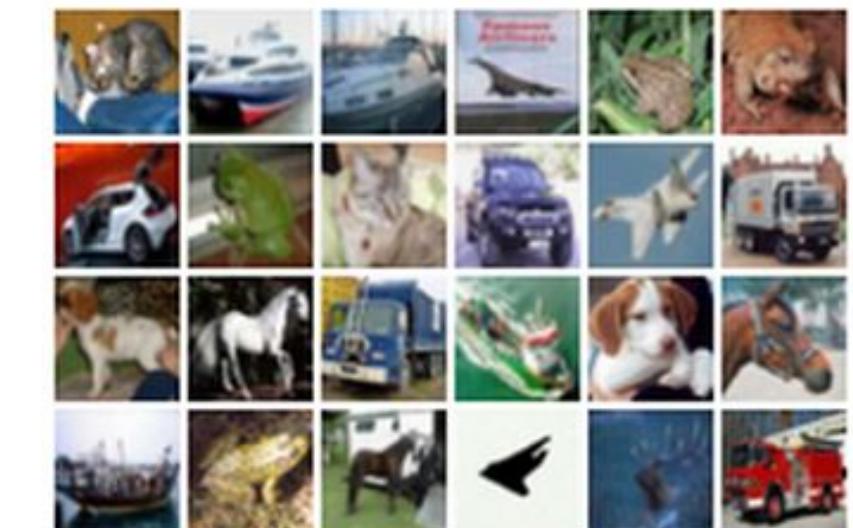
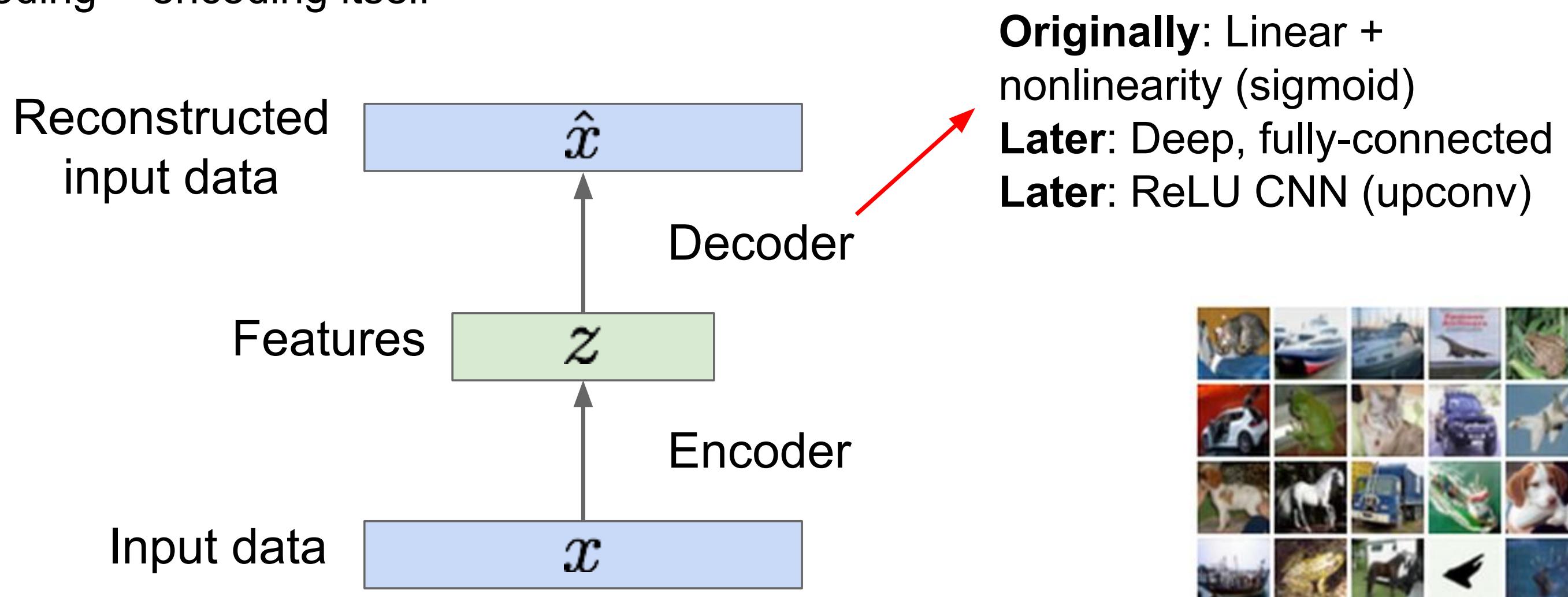


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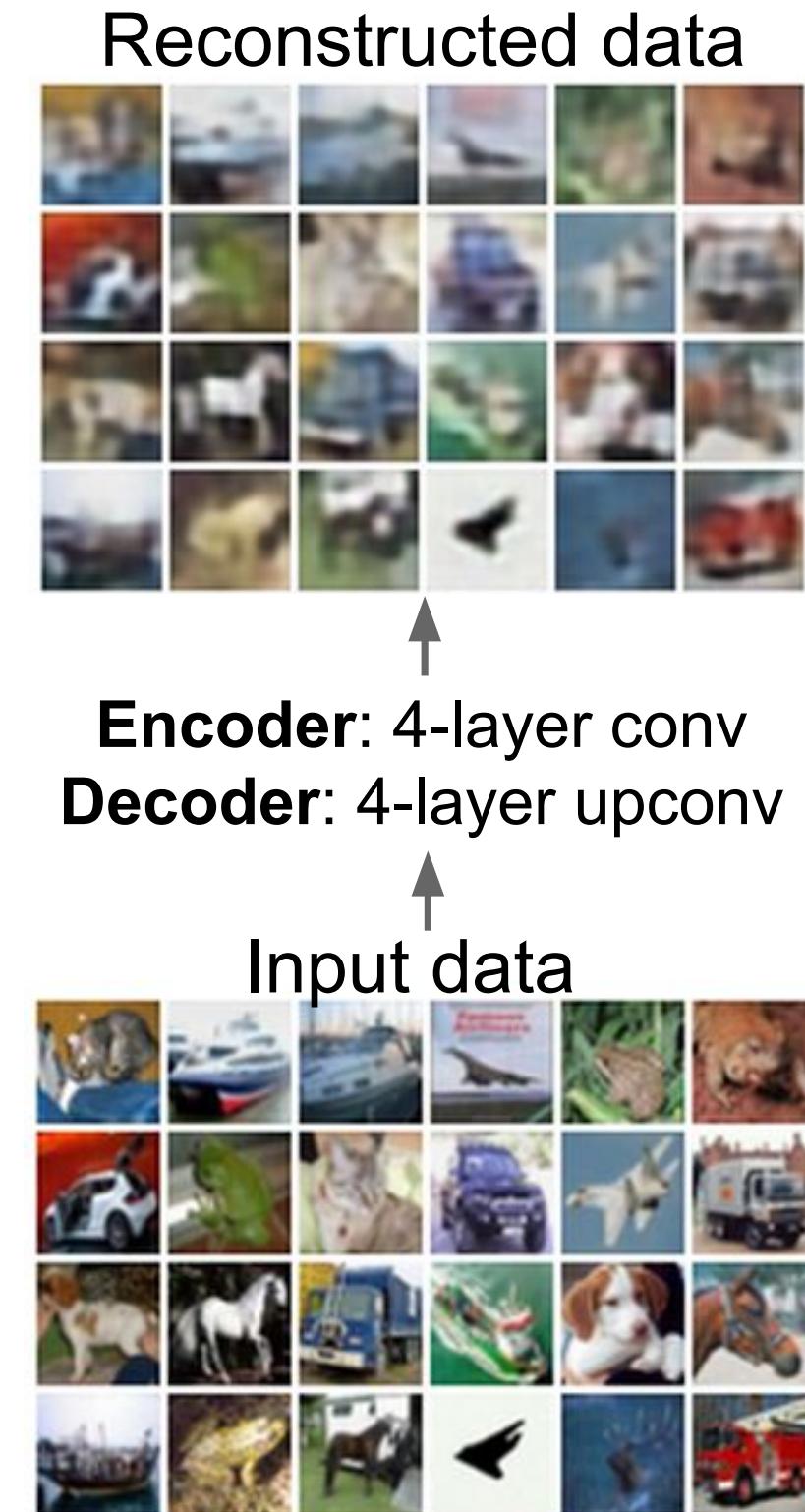
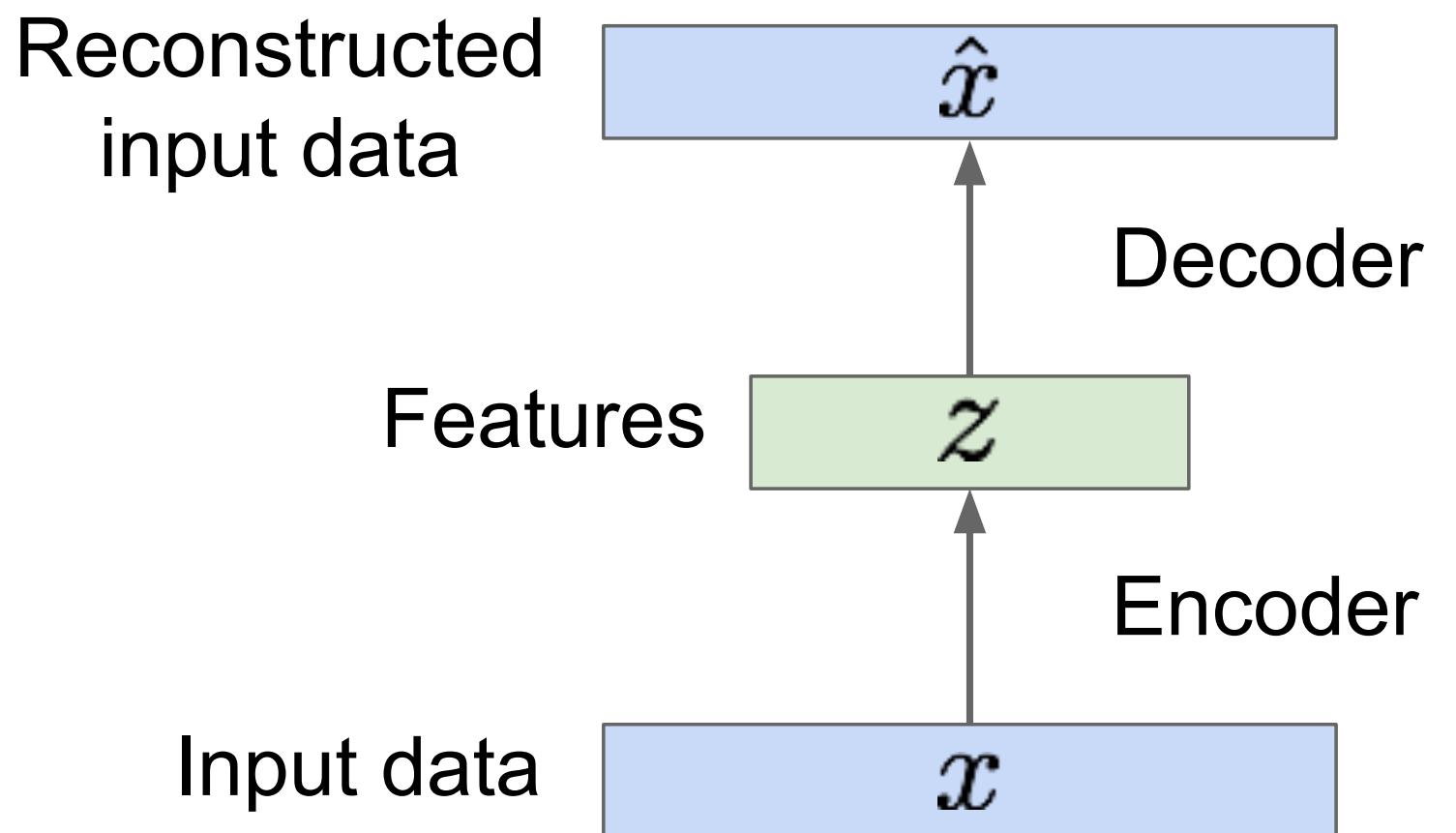


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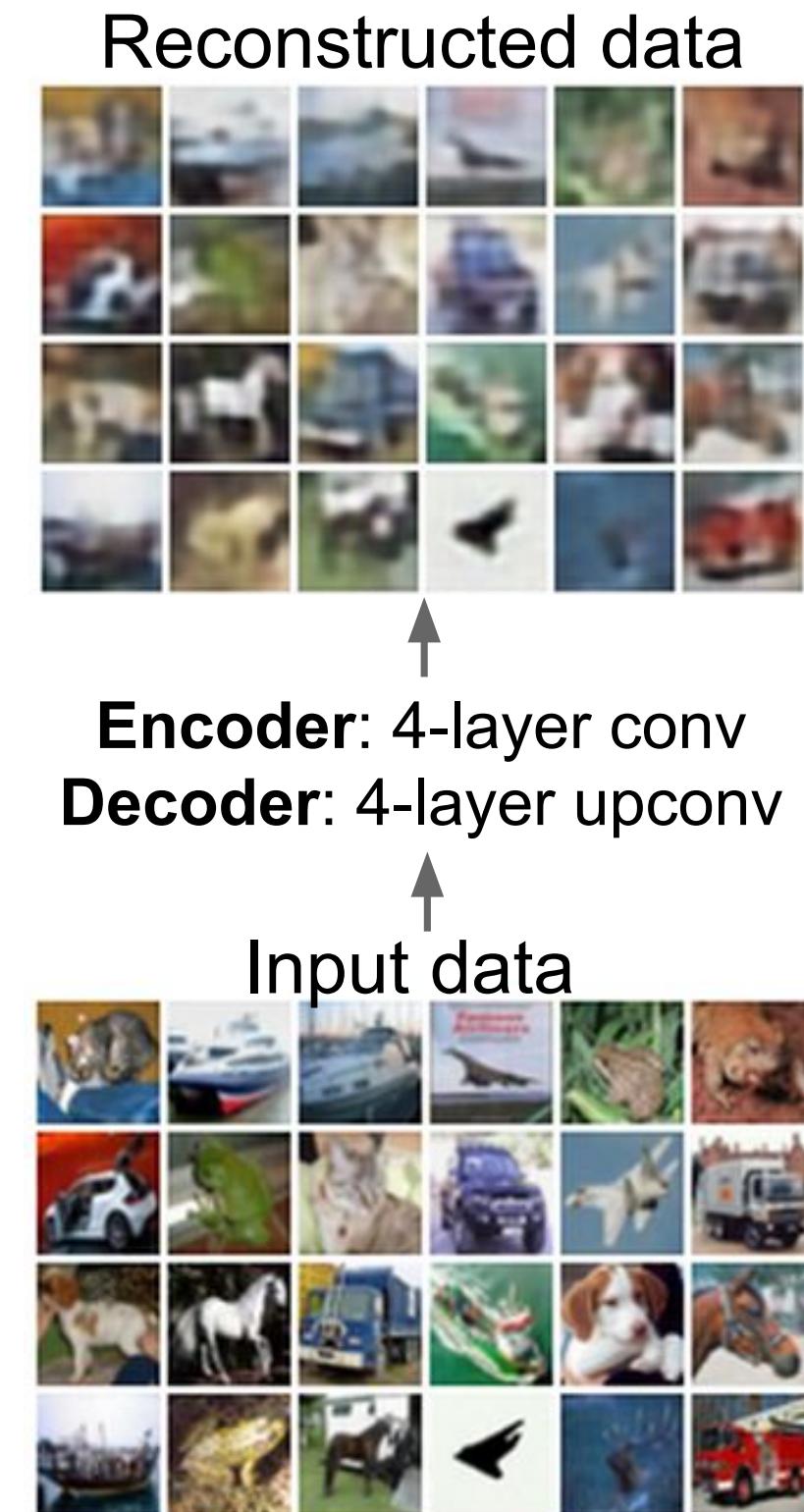
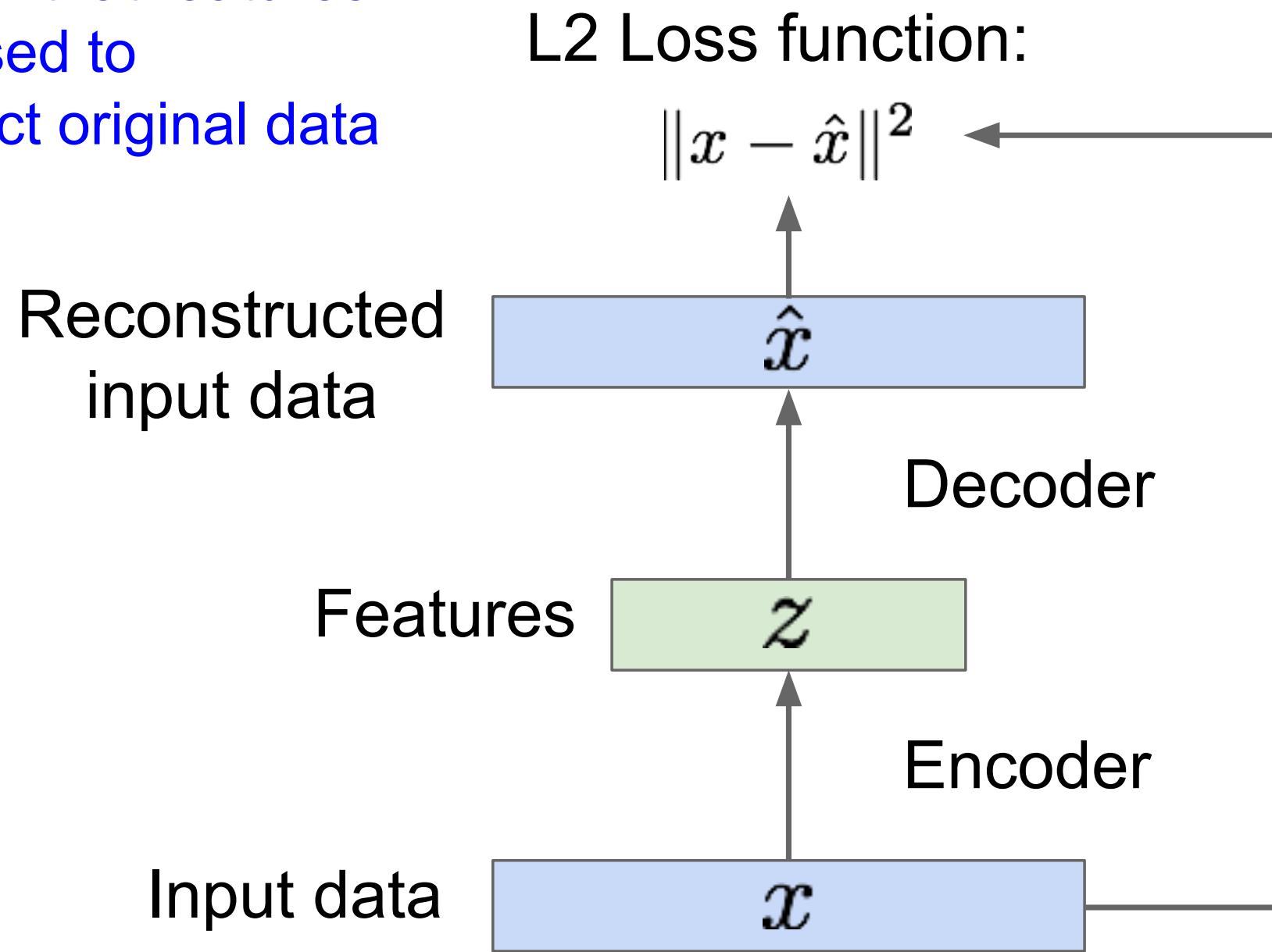
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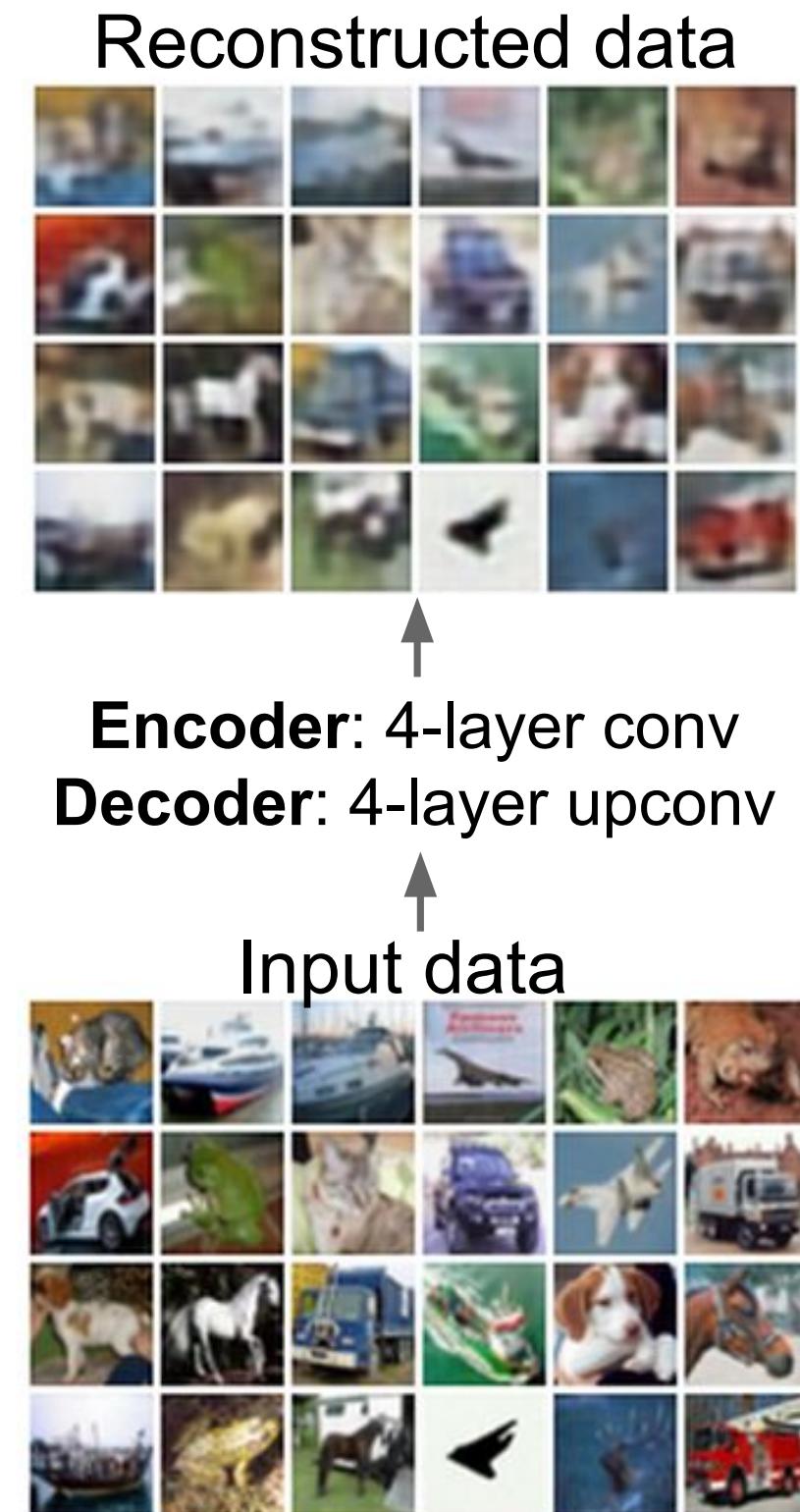
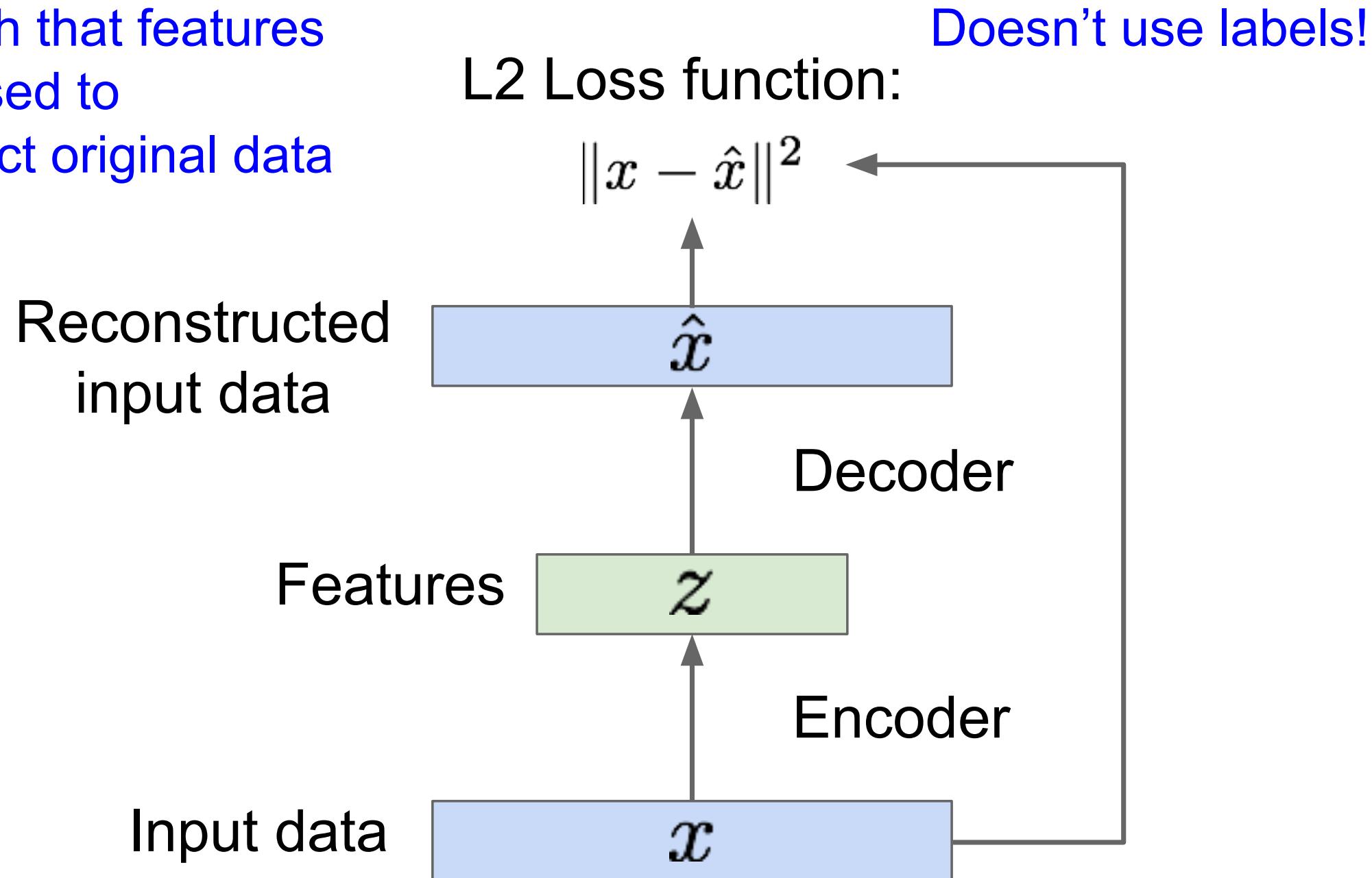
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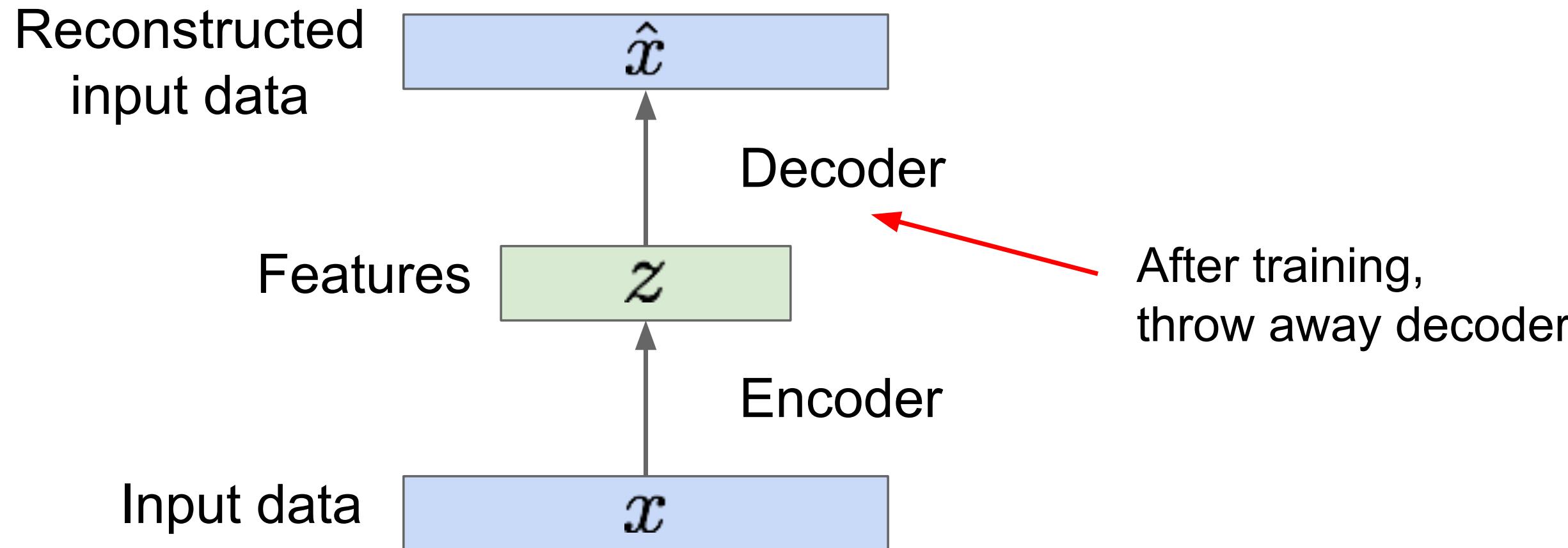


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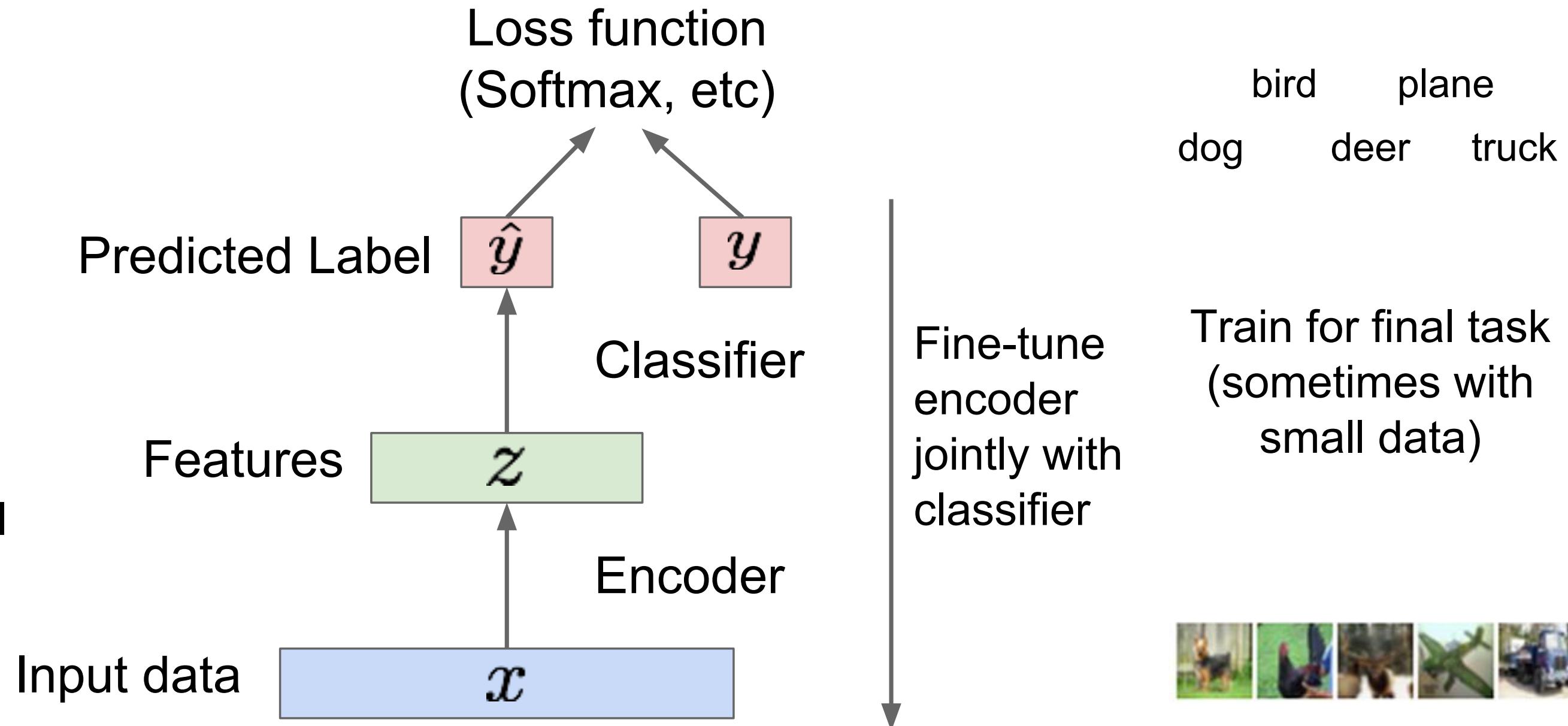


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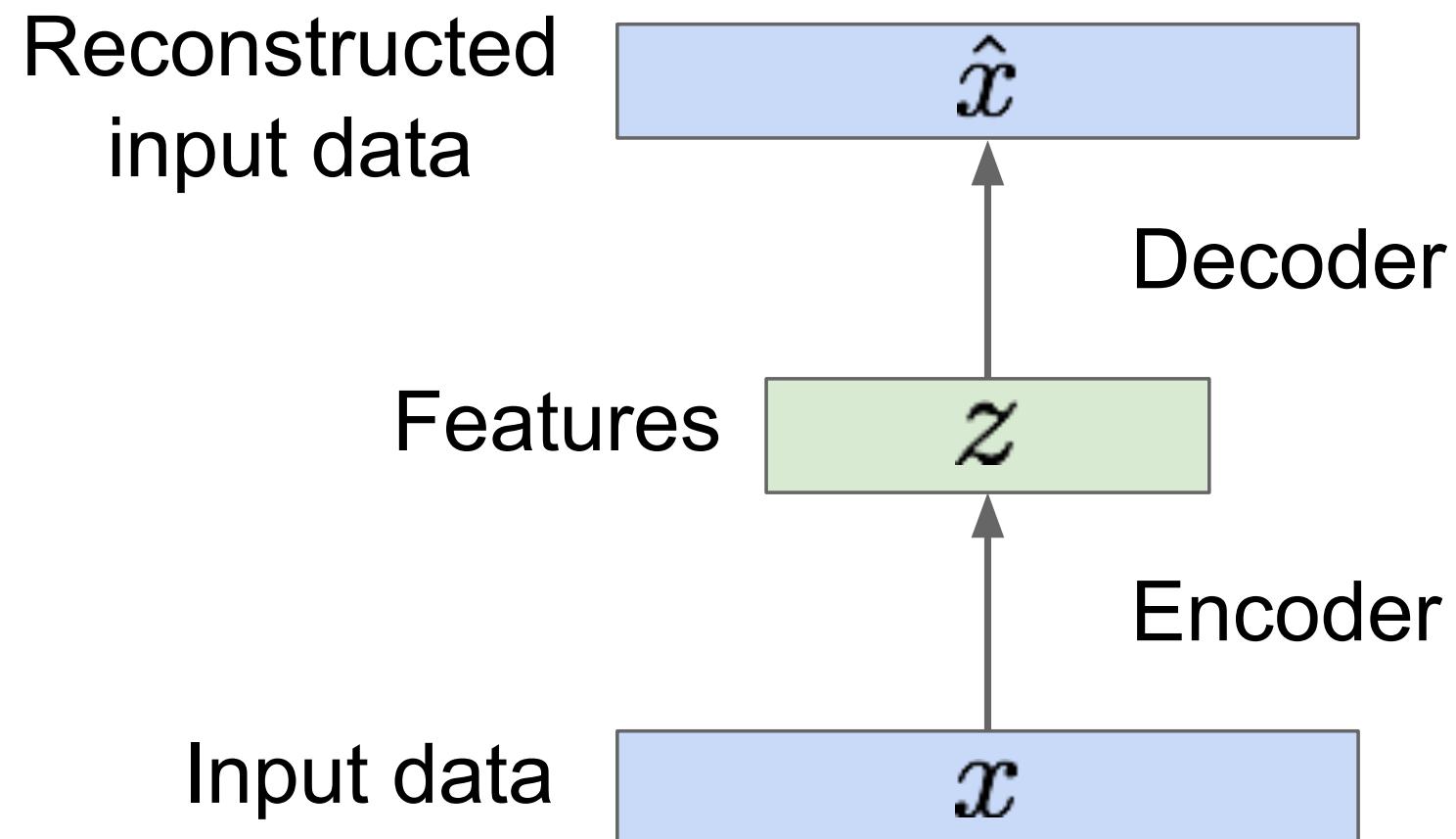
# Some background first: Autoencoders

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



# Some background first: 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

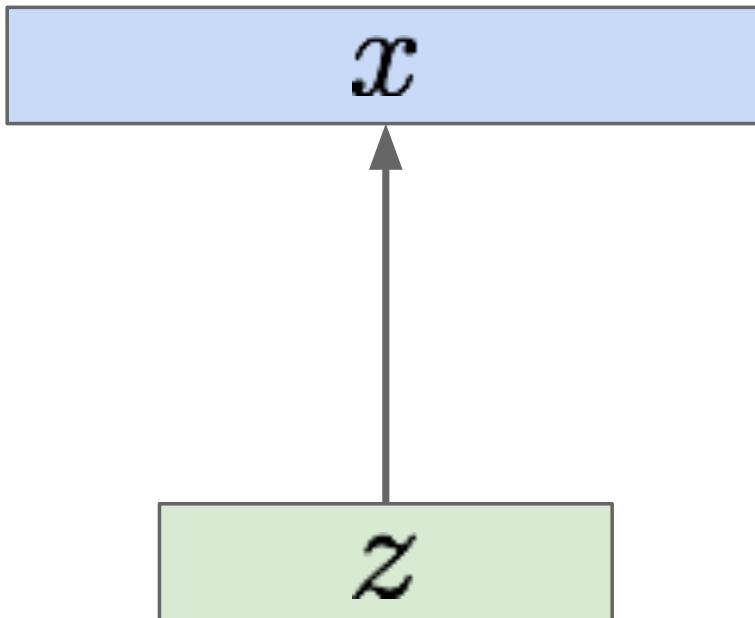
Probabilistic spin on autoencoders - will let us sample from the model to generate data!

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

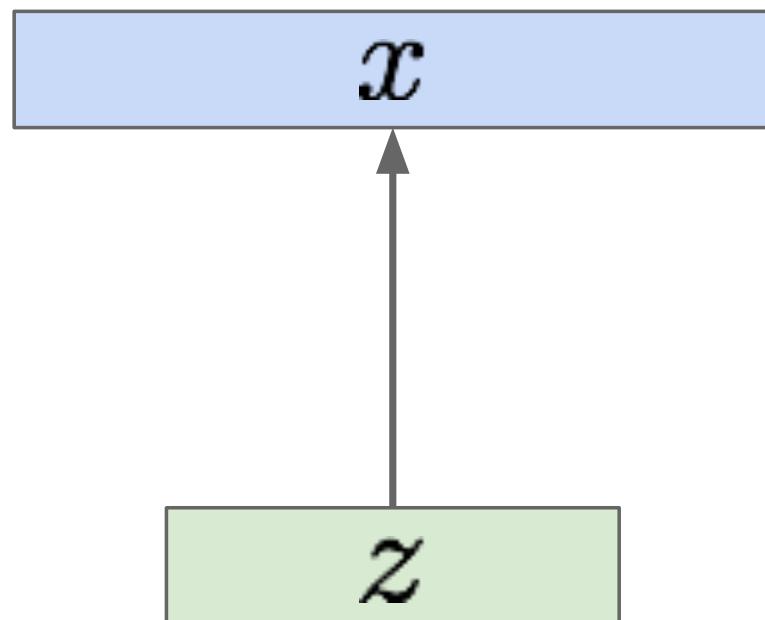
Kingma and Welling, "Auto-Encoding Variational Bayes", ICLR 2014

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

# Variational Autoencoders

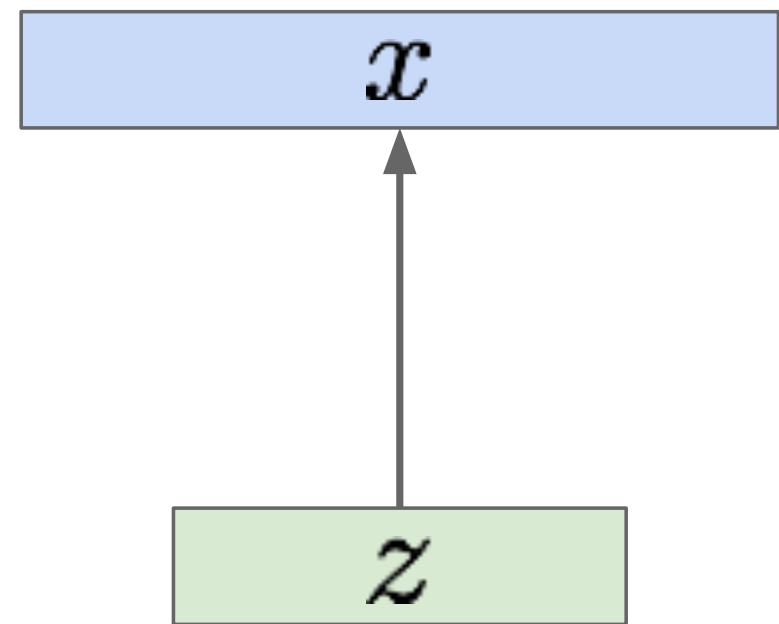
We want to estimate the true parameters  $\theta^*$  of this generative model.

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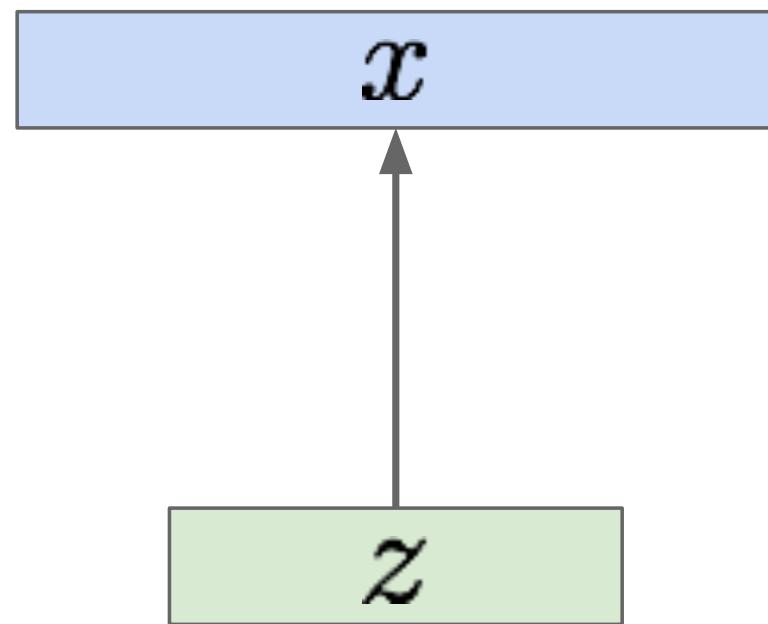
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How should we represent this model?

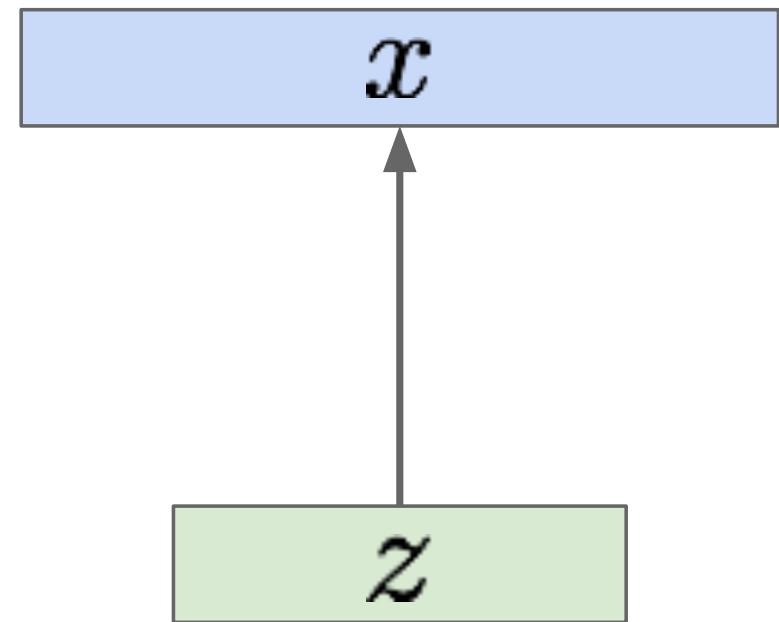
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How should we represent this model?

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

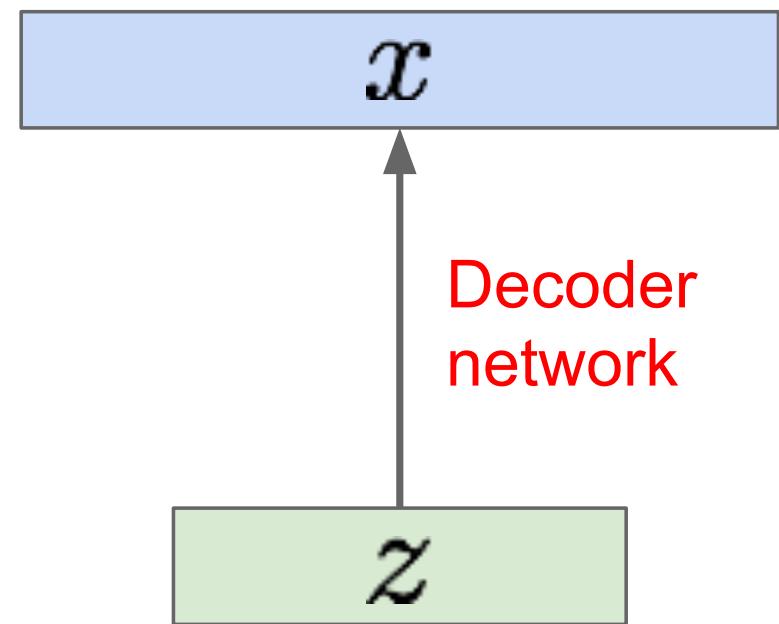
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Conditional  $p(x|z)$  is complex (generates  
image) => represent with neural network

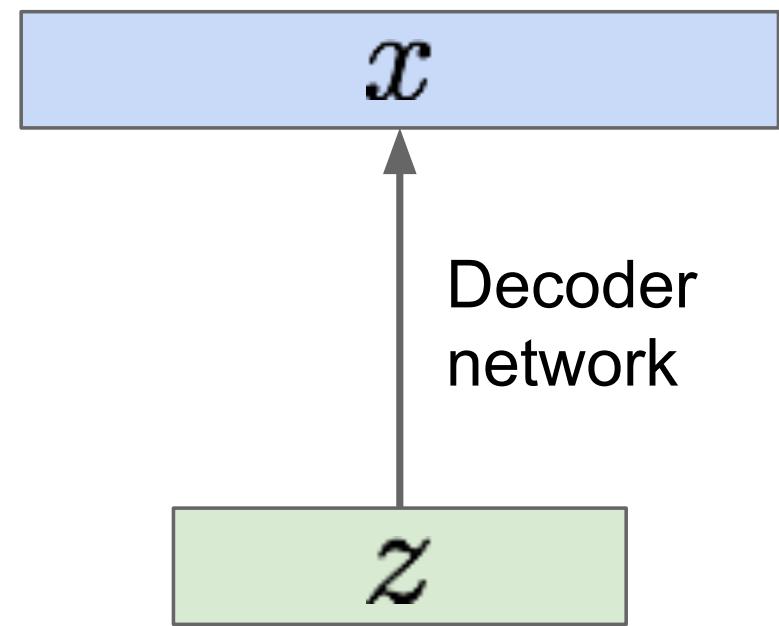
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How to train the model?

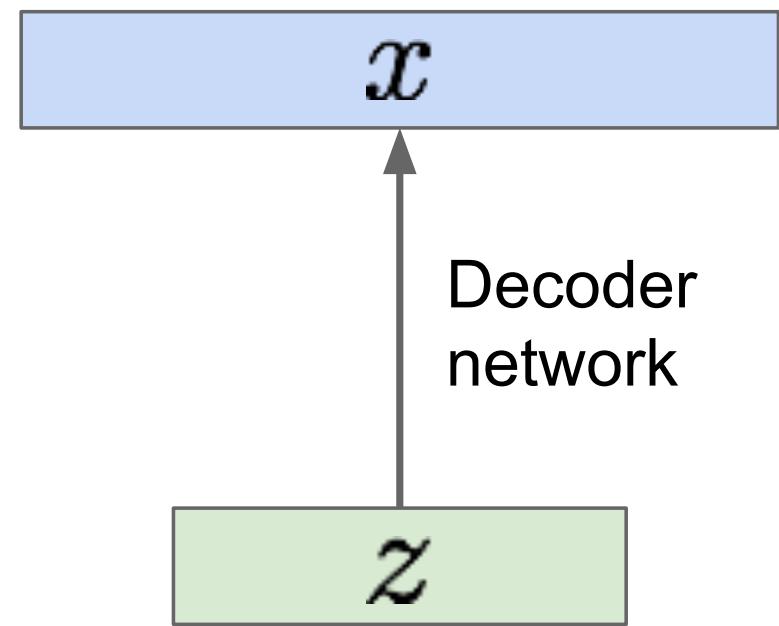
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How to train the model?

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

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

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

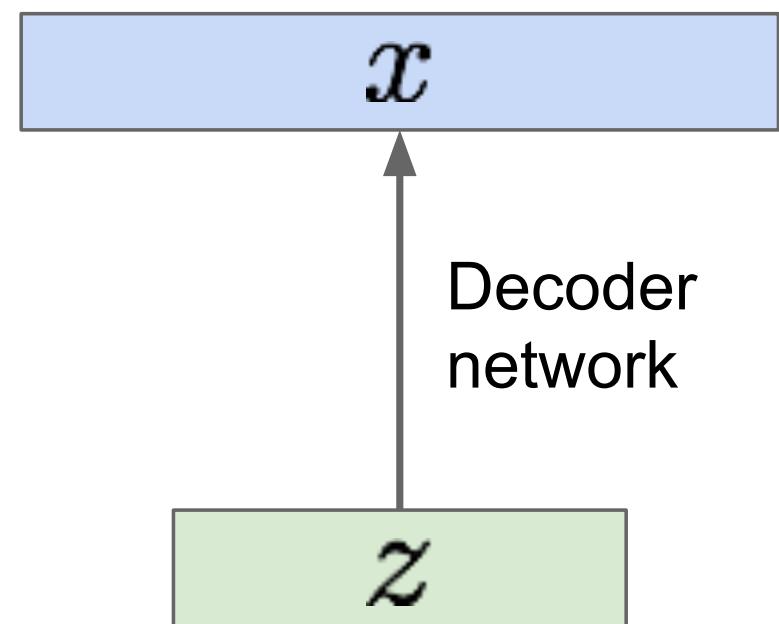
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Now with latent  $z$

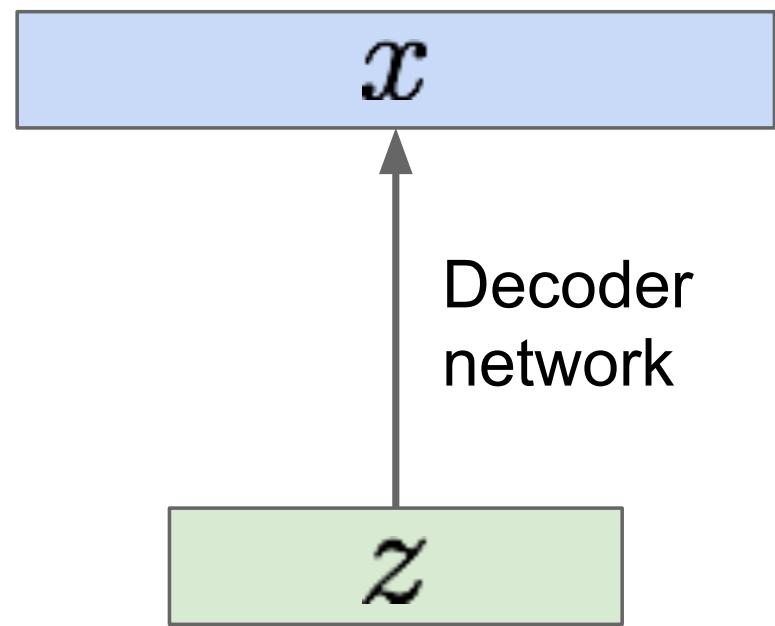
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$$p_{\theta}(x) = \int p_{\theta}(z)p_{\theta}(x|z)dz$$

Q: What is the problem with this?

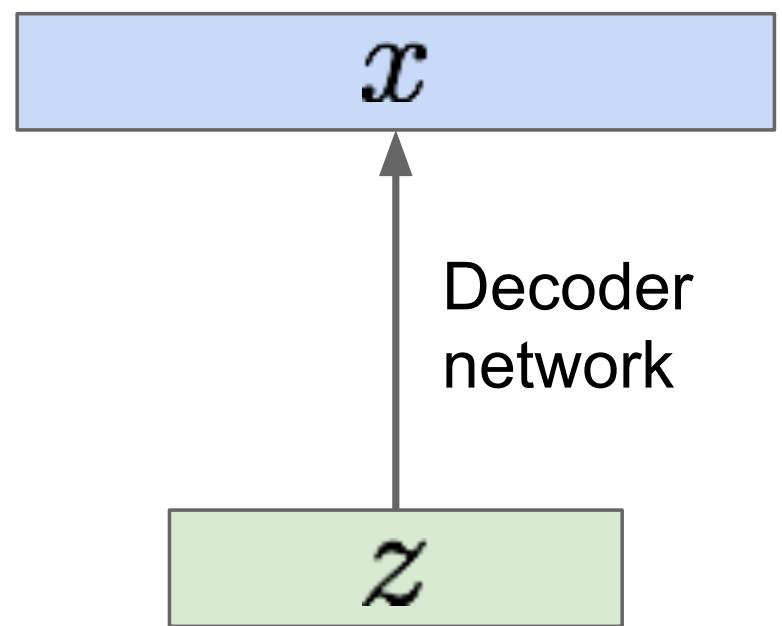
# Variational Autoencoders

Sample from  
true conditional

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

Sample from  
true prior

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



We want to estimate the true parameters  $\theta^*$  of this generative model.

How to train the model?

Remember strategy for training generative models from FVBMs. 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:  $p_{\theta}(x) = \int p_{\theta}(z)p_{\theta}(x|z)dz$

# Variational Autoencoders: Intractability

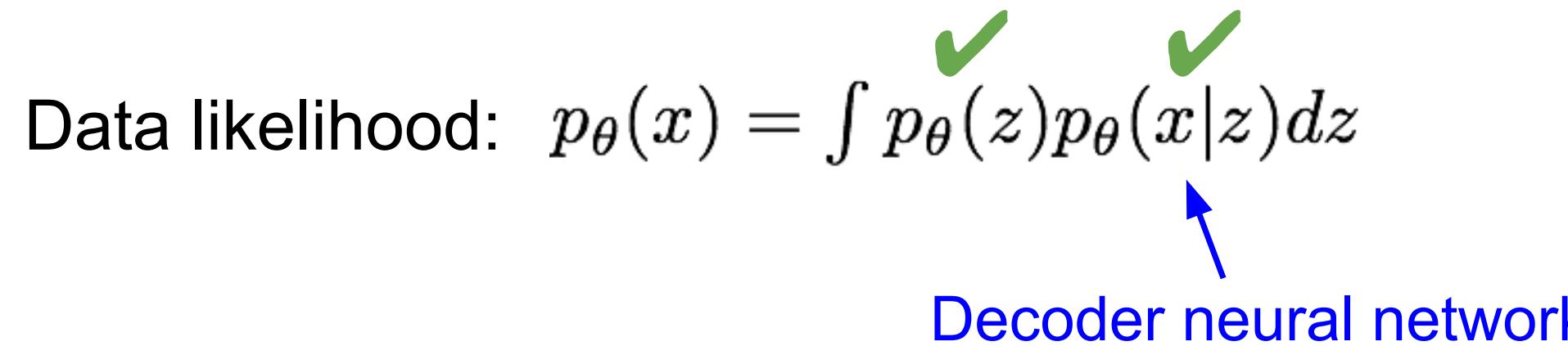
Data likelihood:  $p_{\theta}(x) = \int p_{\theta}(z)p_{\theta}(x|z)dz$



Simple Gaussian prior

# Variational Autoencoders: Intractability

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



Decoder neural network

# 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  $z$ !

# Variational Autoencoders: Intractability



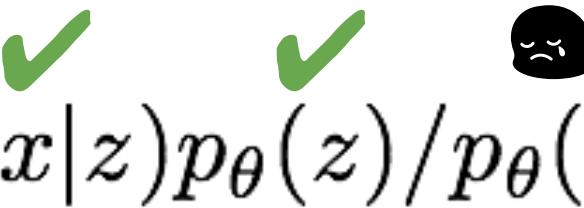
Data likelihood:  $p_\theta(x) = \int p_\theta(z)p_\theta(x|z)dz$

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

# Variational Autoencoders: Intractability

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

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



Intractable data likelihood

# Variational Autoencoders: Intractability

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

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

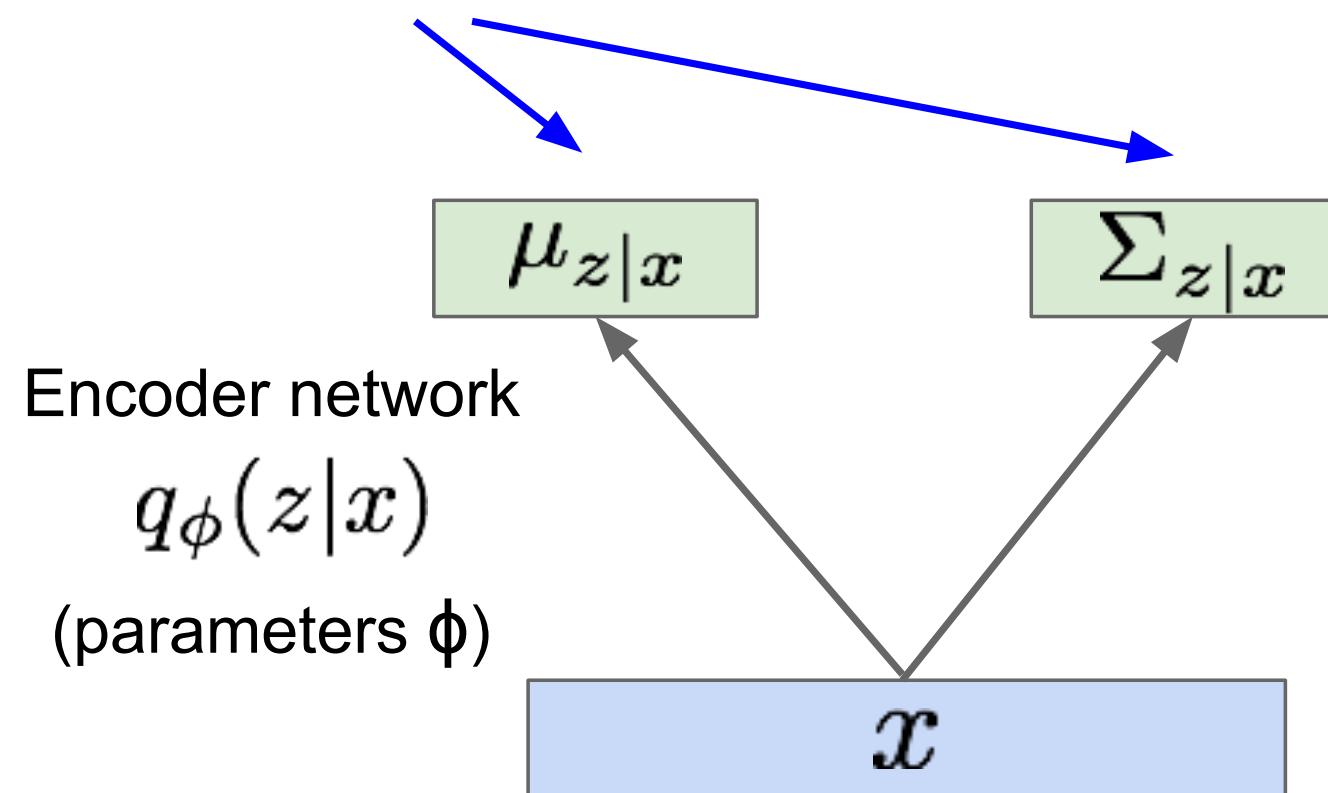
Solution: In addition to decoder network modeling  $p_\theta(x|z)$ , define additional encoder network  $q_\phi(z|x)$  that approximates  $p_\theta(z|x)$

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

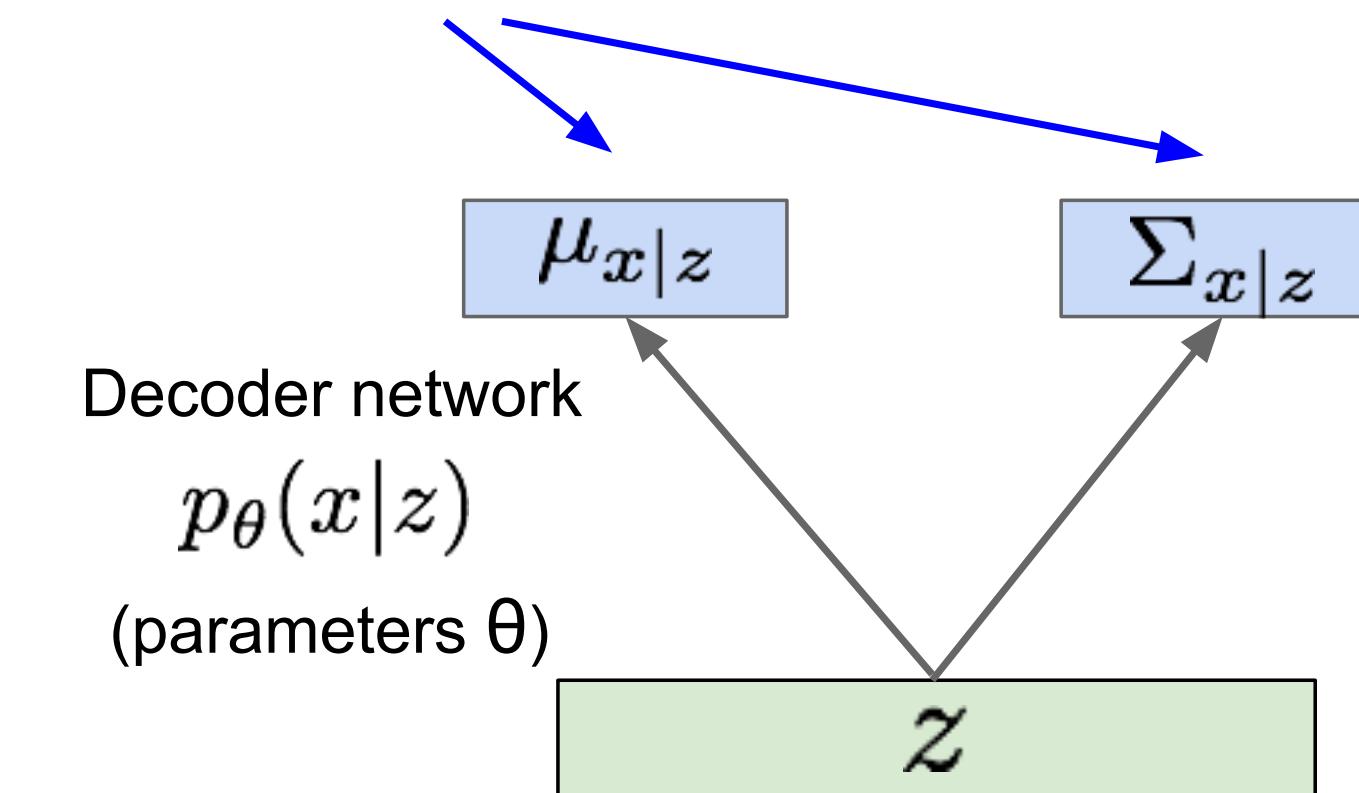
# Variational Autoencoders

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

Mean and (diagonal) covariance of  $\mathbf{z} | \mathbf{x}$

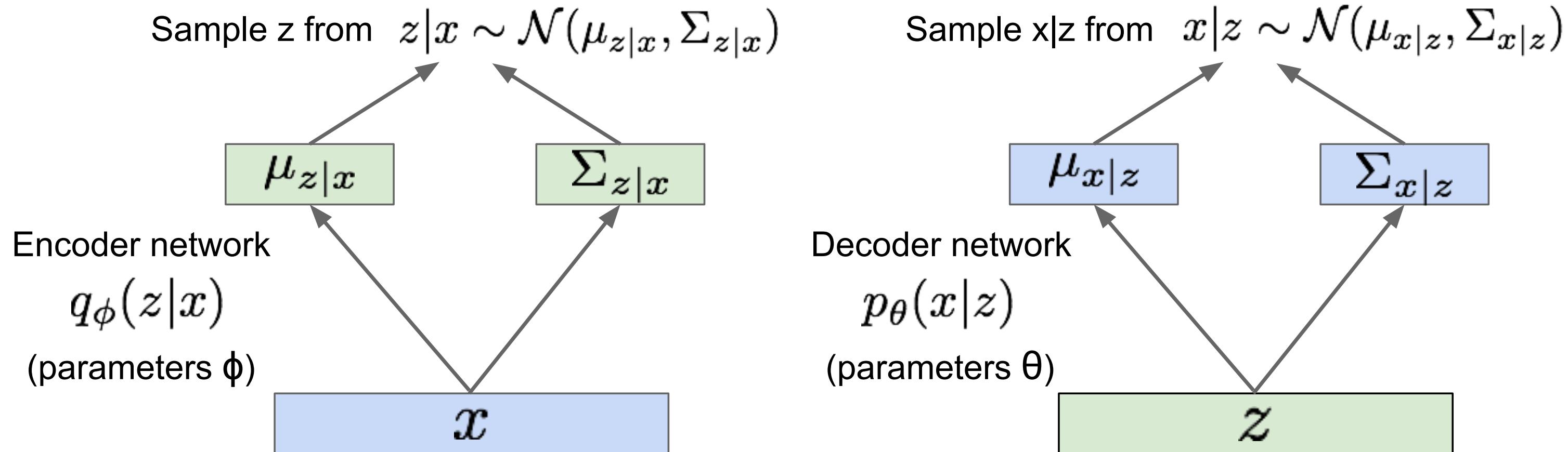


Mean and (diagonal) covariance of  $\mathbf{x} | \mathbf{z}$



# Variational Autoencoders

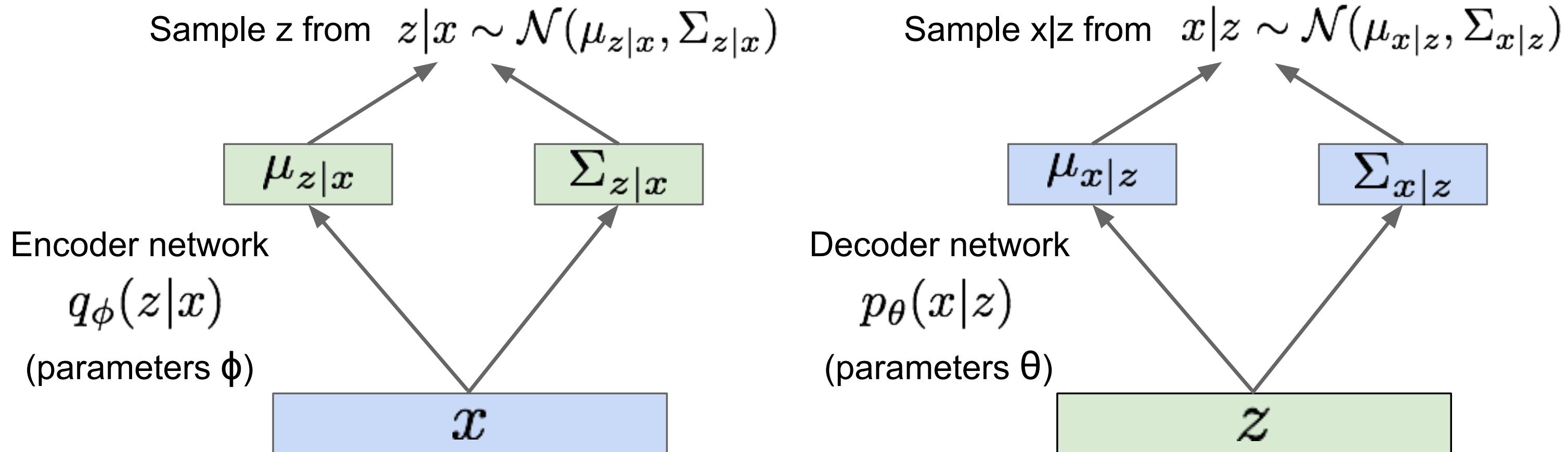
Since we're modeling probabilistic generation of data, encoder and decoder networks are probabilistic



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



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:

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

# Variational Autoencoders

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


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:

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

# Variational Autoencoders

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# Variational Autoencoders

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# Variational Autoencoders

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

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# Variational Autoencoders

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

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

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

# Variational Autoencoders

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

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↑  
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  $\geq 0$ .

# Variational Autoencoders

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

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

# Variational Autoencoders

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

$$\begin{aligned}\log p_\theta(x^{(i)}) &= \mathbf{E}_{z \sim q_\phi(z|x^{(i)})} [\log p_\theta(x^{(i)})] \quad (p_\theta(x^{(i)}) \text{ Does not depend on } z) \\ &= \mathbf{E}_z \left[ \log \frac{p_\theta(x^{(i)} | z)p_\theta(z)}{p_\theta(z | x^{(i)})} \right] \quad (\text{Bayes' Rule}) \\ &= \mathbf{E}_z \left[ \log \frac{p_\theta(x^{(i)} | z)p_\theta(z)}{p_\theta(z | x^{(i)})} \frac{q_\phi(z | x^{(i)})}{q_\phi(z | x^{(i)})} \right] \quad (\text{Multiply by constant}) \\ &= \mathbf{E}_z [\log p_\theta(x^{(i)} | z)] - \mathbf{E}_z \left[ \log \frac{q_\phi(z | x^{(i)})}{p_\theta(z)} \right] + \mathbf{E}_z \left[ \log \frac{q_\phi(z | x^{(i)})}{p_\theta(z | x^{(i)})} \right] \quad (\text{Logarithms}) \\ &= \underbrace{\mathbf{E}_z [\log p_\theta(x^{(i)} | z)]}_{\mathcal{L}(x^{(i)}, \theta, \phi)} - D_{KL}(q_\phi(z | x^{(i)}) || p_\theta(z)) + \underbrace{D_{KL}(q_\phi(z | x^{(i)}) || p_\theta(z | x^{(i)}))}_{> 0}\end{aligned}$$

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

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:

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

$$= \mathbf{E}_z \left[ \log \frac{p_\theta(x^{(i)} | z)p_\theta(z)}{p_\theta(z | x^{(i)})} \right] \quad (\text{Bayes' Rule})$$

Reconstruct  
the input data

$$= \mathbf{E}_z \left[ \log \frac{p_\theta(x^{(i)} | z)p_\theta(z)}{p_\theta(z | x^{(i)})} \frac{q_\phi(z | x^{(i)})}{q_\phi(z | x^{(i)})} \right] \quad (\text{Multiply by constant})$$

Make approximate  
posterior distribution  
close to prior

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

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Training: Maximize lower bound

# Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

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

# Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

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

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

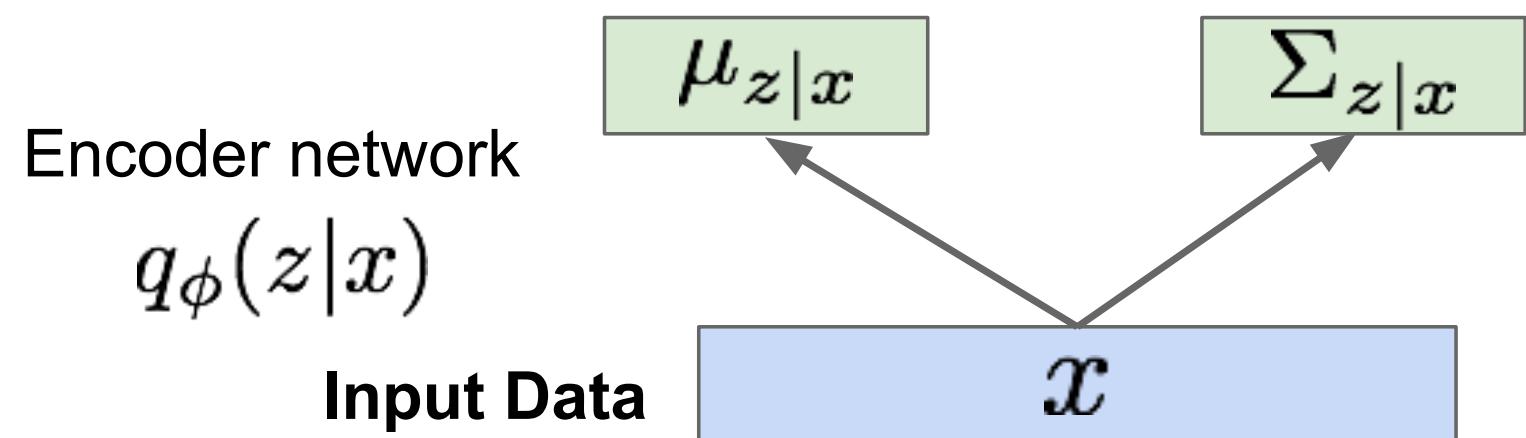
Input Data

$x$

# Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

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



# Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

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

Make approximate posterior distribution close to prior

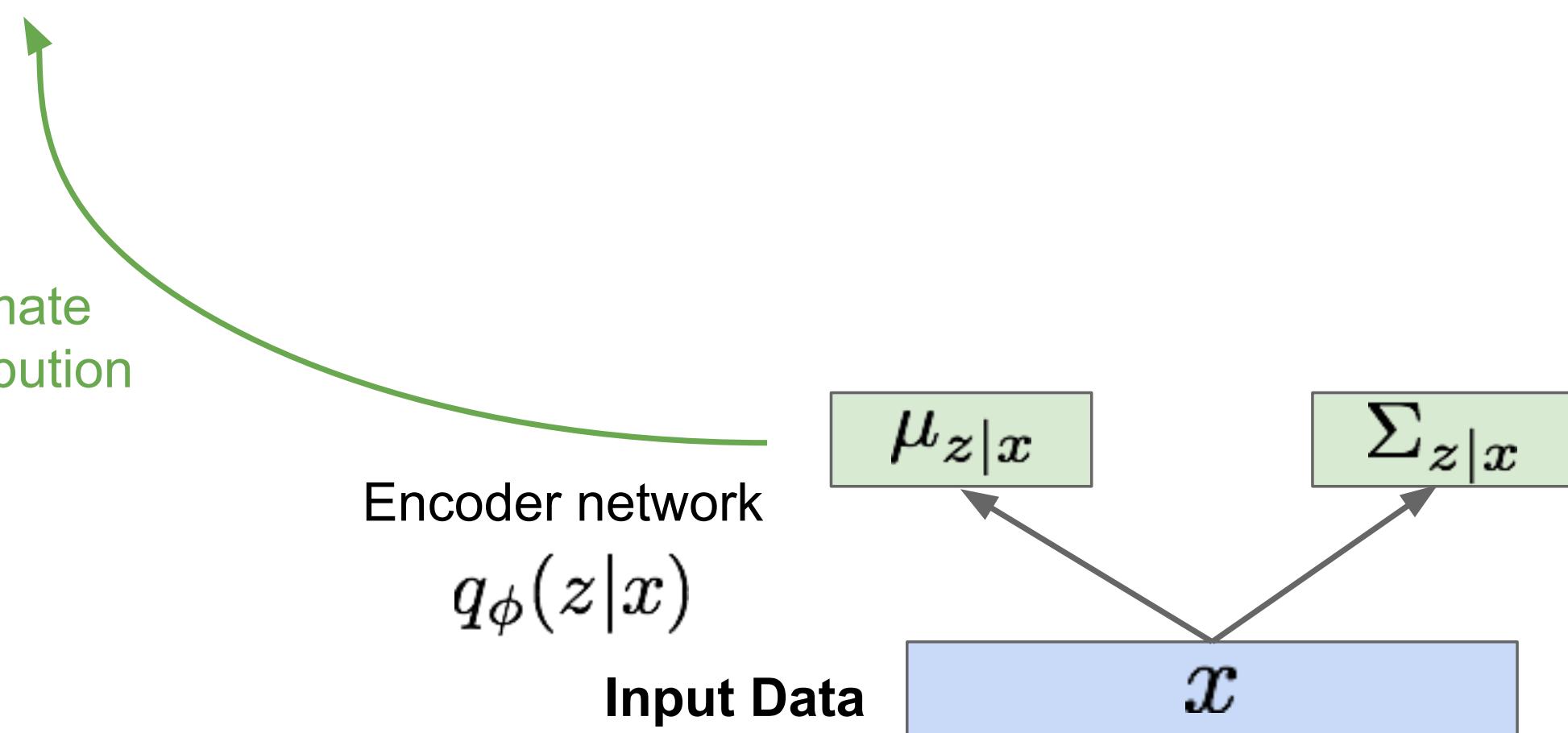
Encoder network

$$q_\phi(z|x)$$

Input Data

$$\mu_{z|x}$$

$$\Sigma_{z|x}$$

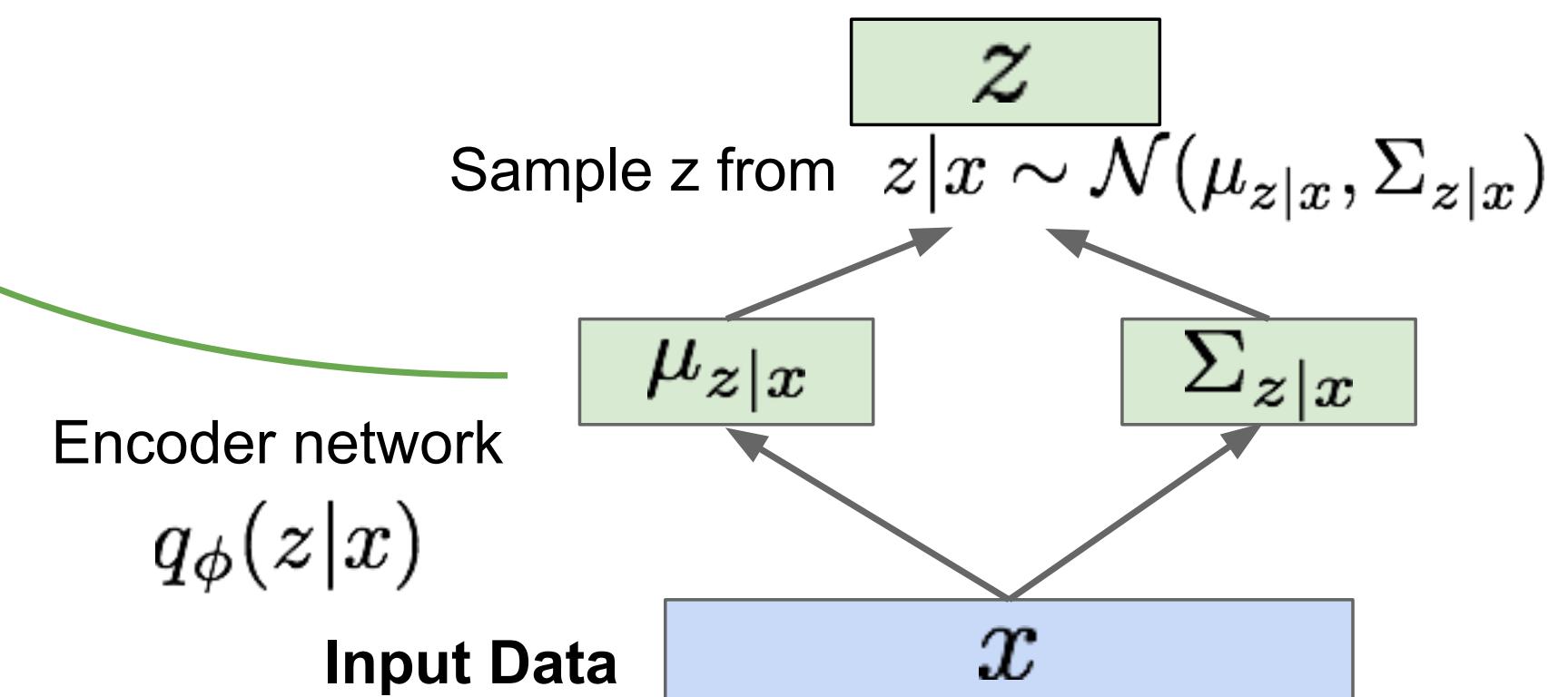


# Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

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

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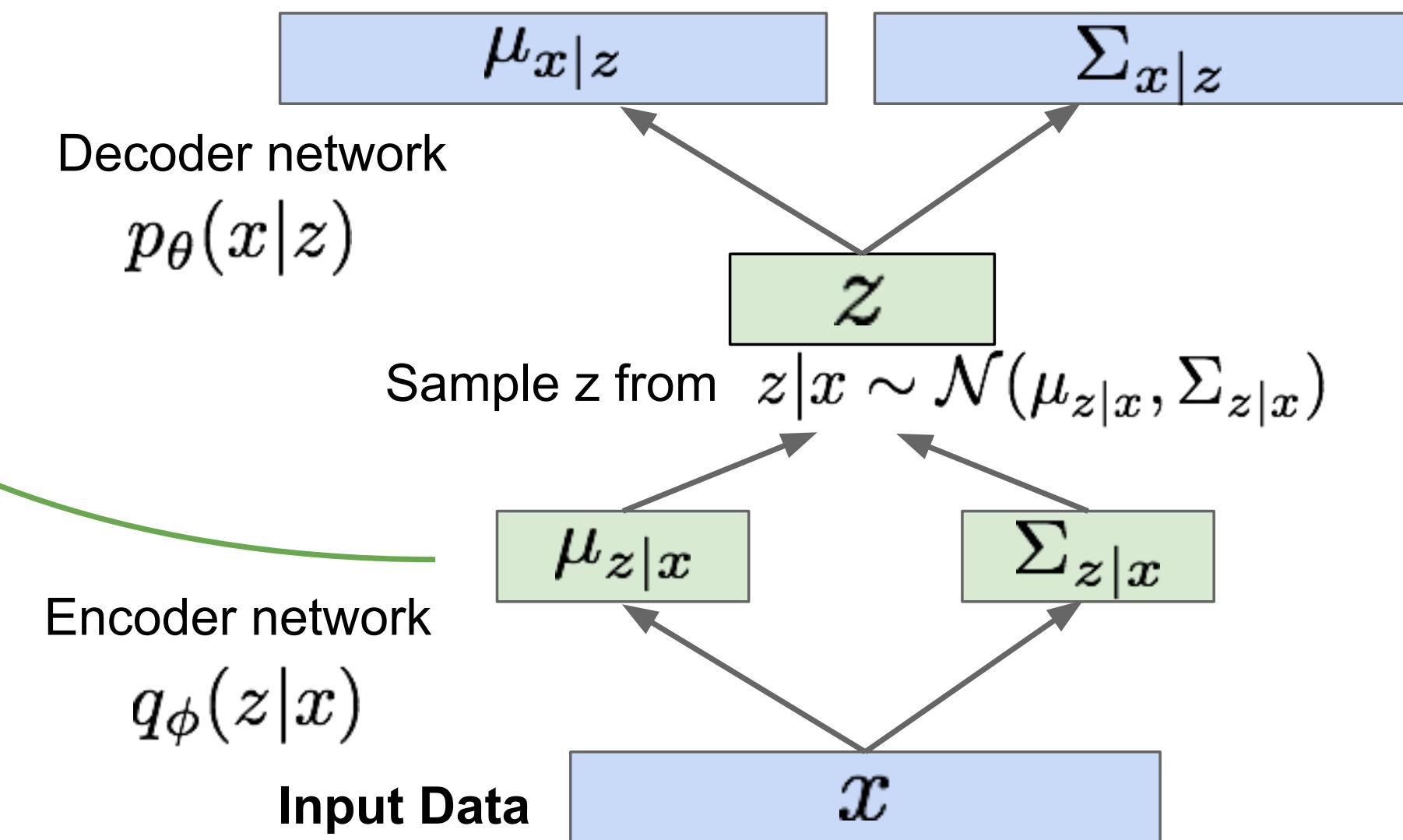


# Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

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

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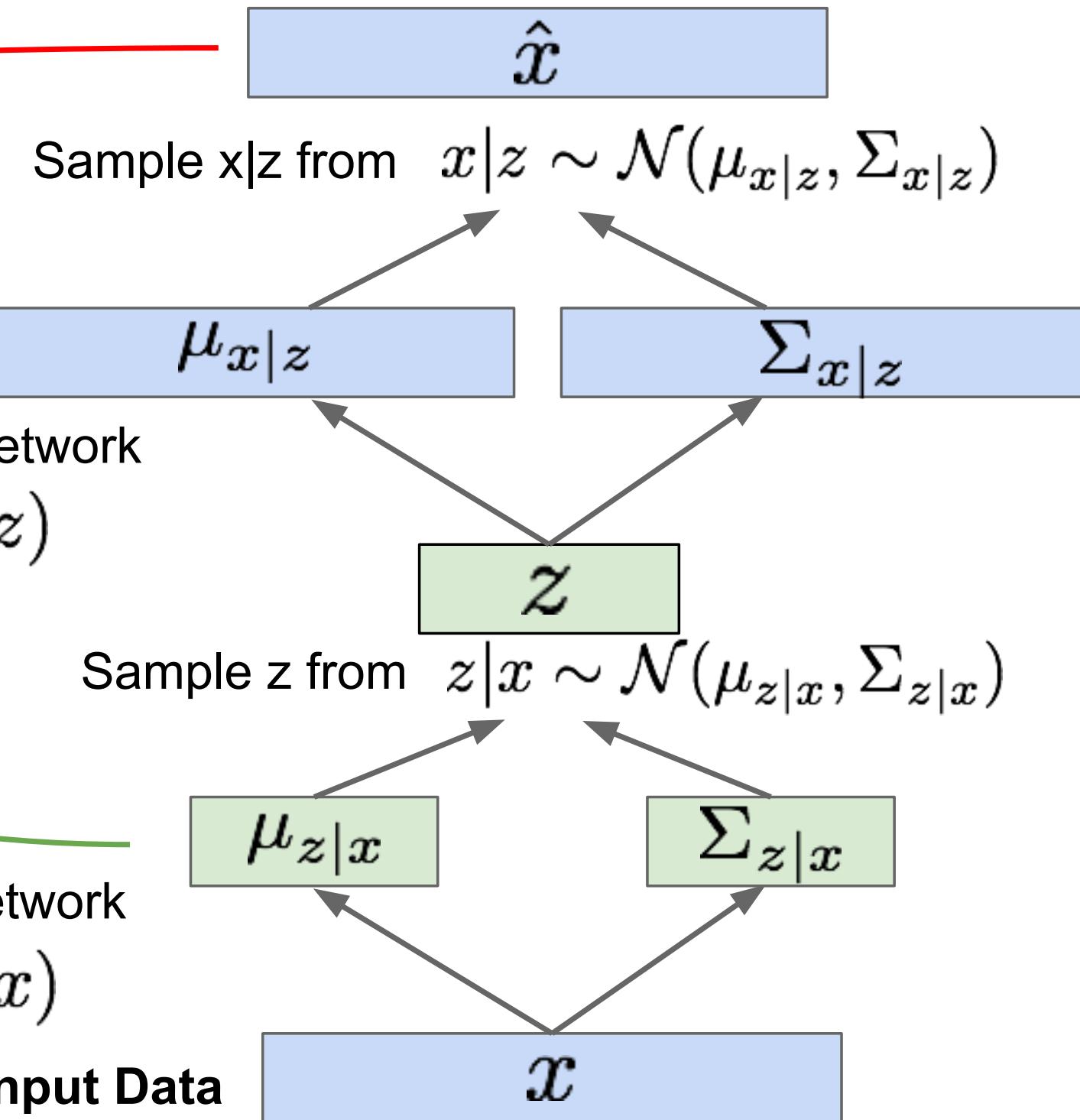
# Variational Autoencoders

Putting it all together: maximizing the likelihood lower bound

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Maximize likelihood of original input being reconstructed

Decoder network  
 $p_\theta(x|z)$



Make approximate posterior distribution close to prior

# Variational Autoencoders

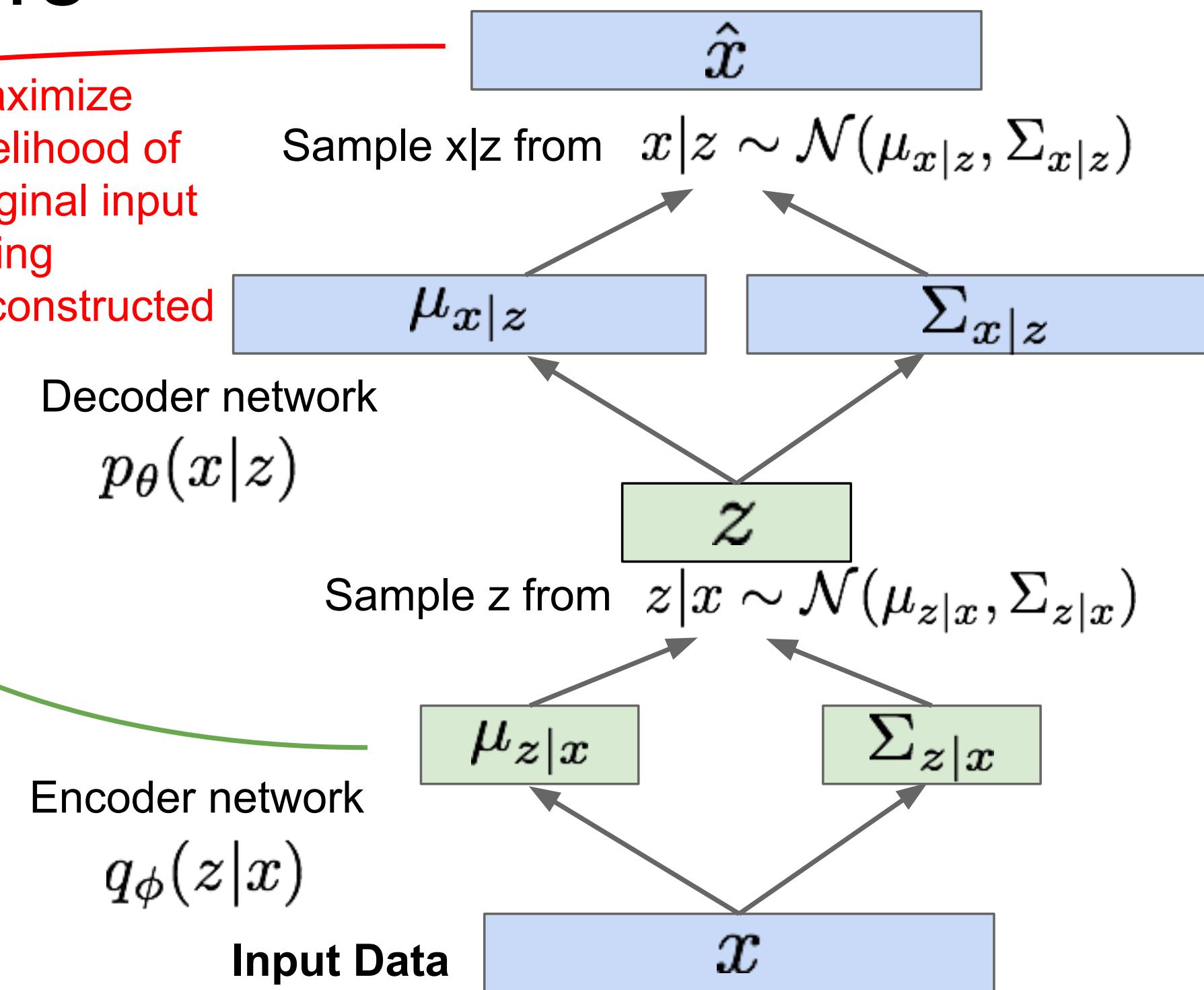
Putting it all together: maximizing the likelihood lower bound

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Maximize likelihood of original input being reconstructed

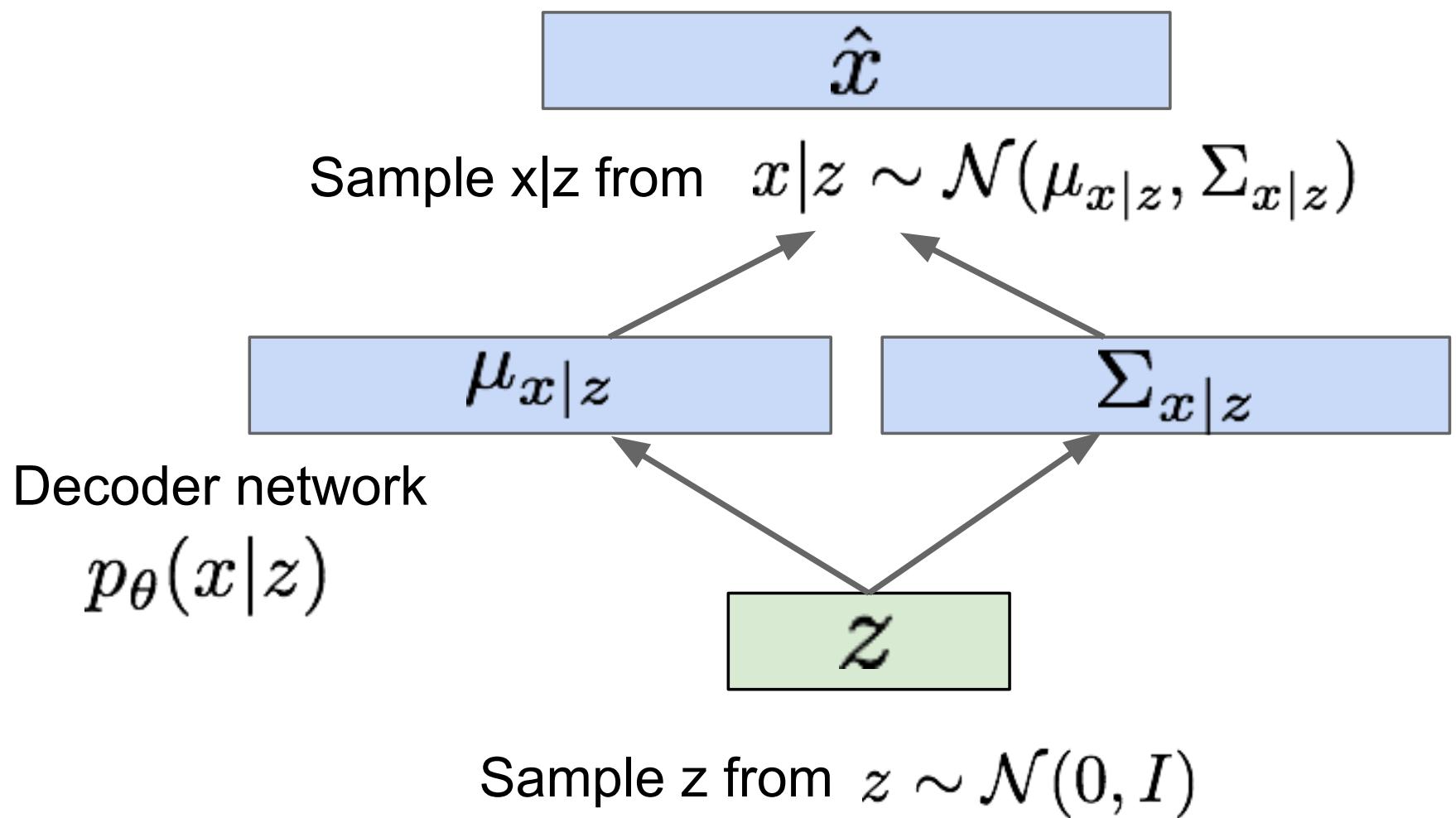
Make approximate posterior distribution close to prior

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



# Variational Autoencoders: Generating Data!

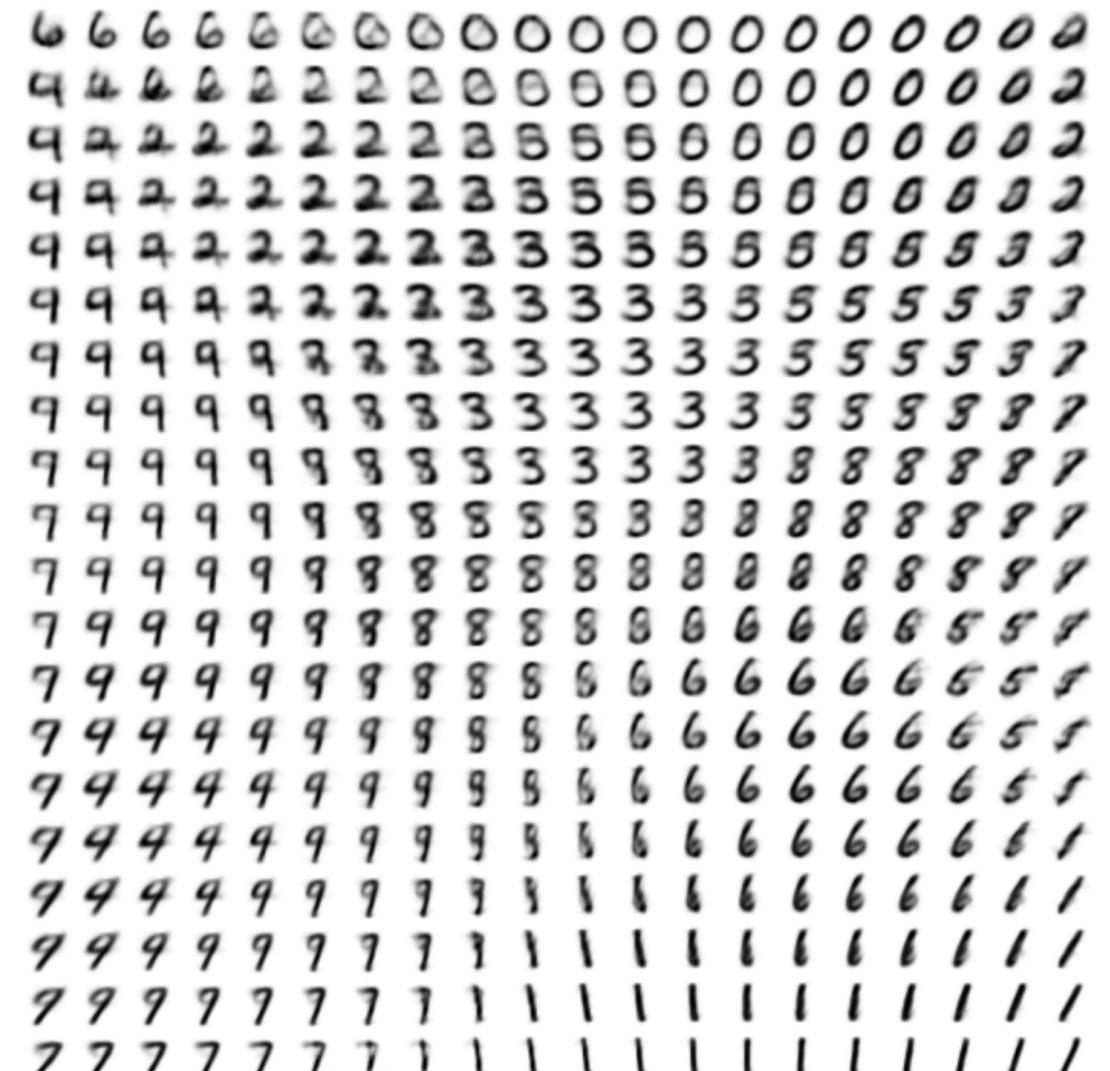
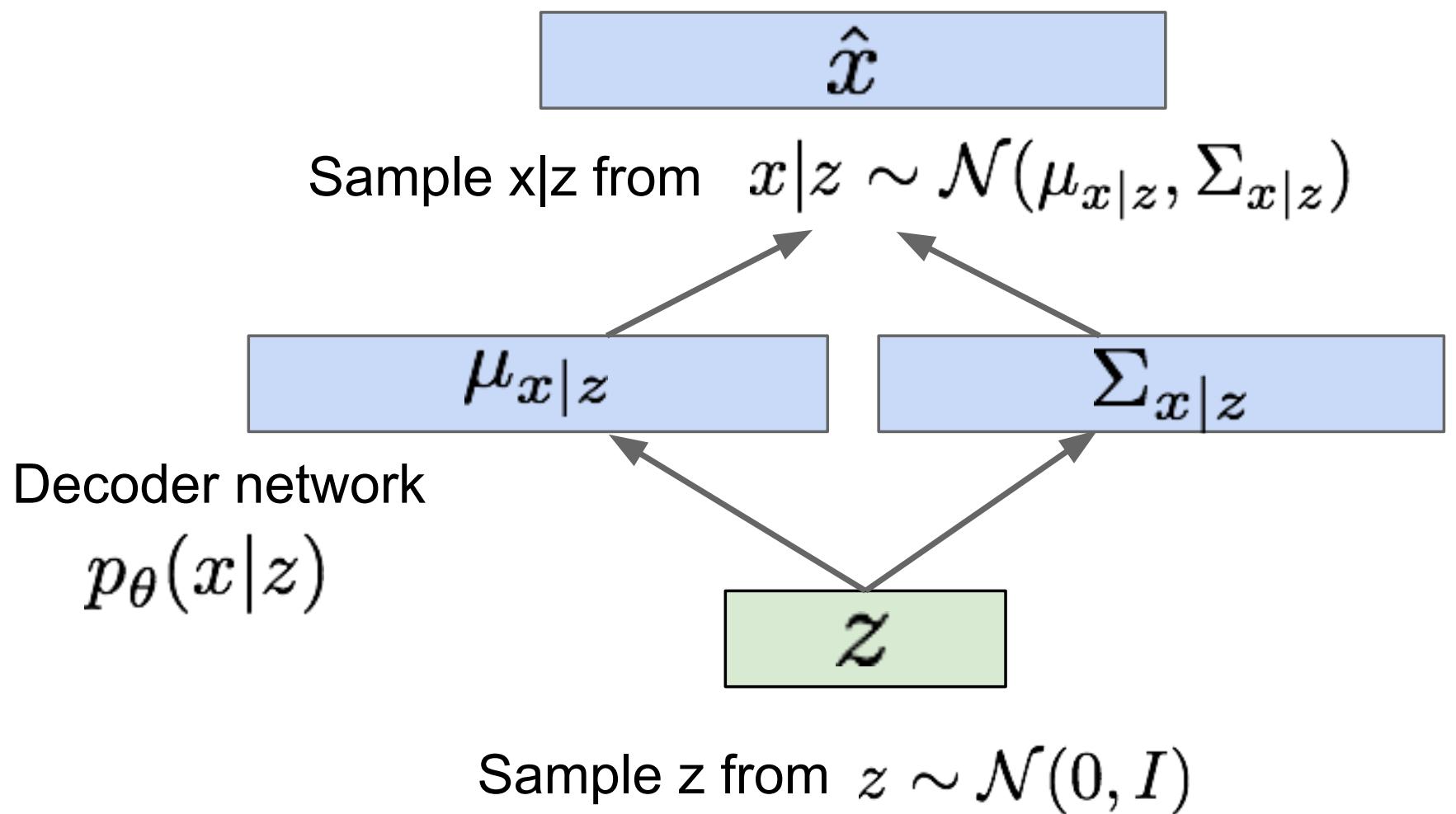
Use decoder network. Now sample z from prior!



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

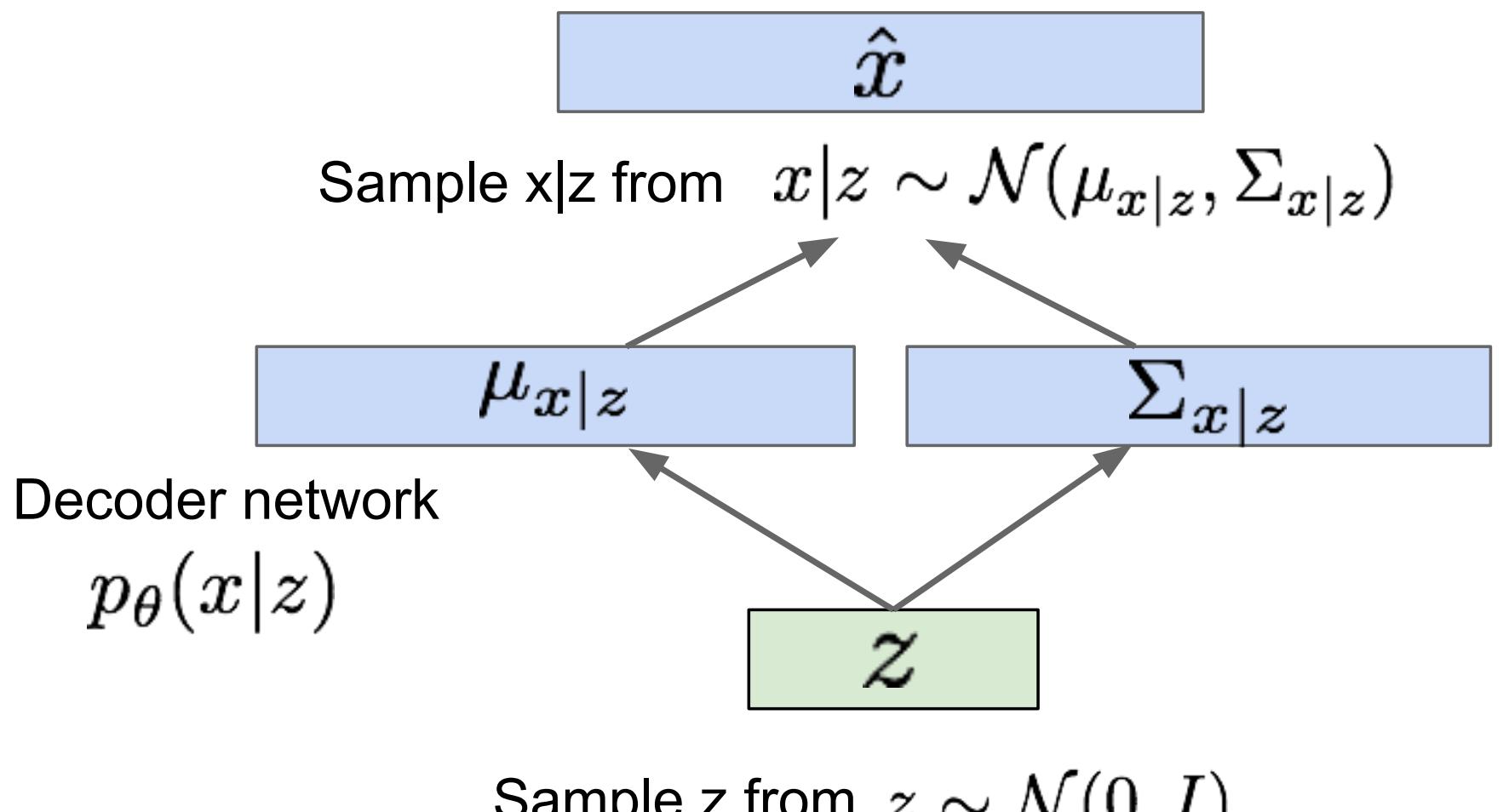
# Variational Autoencoders: Generating Data!

Use decoder network. Now sample z from prior!

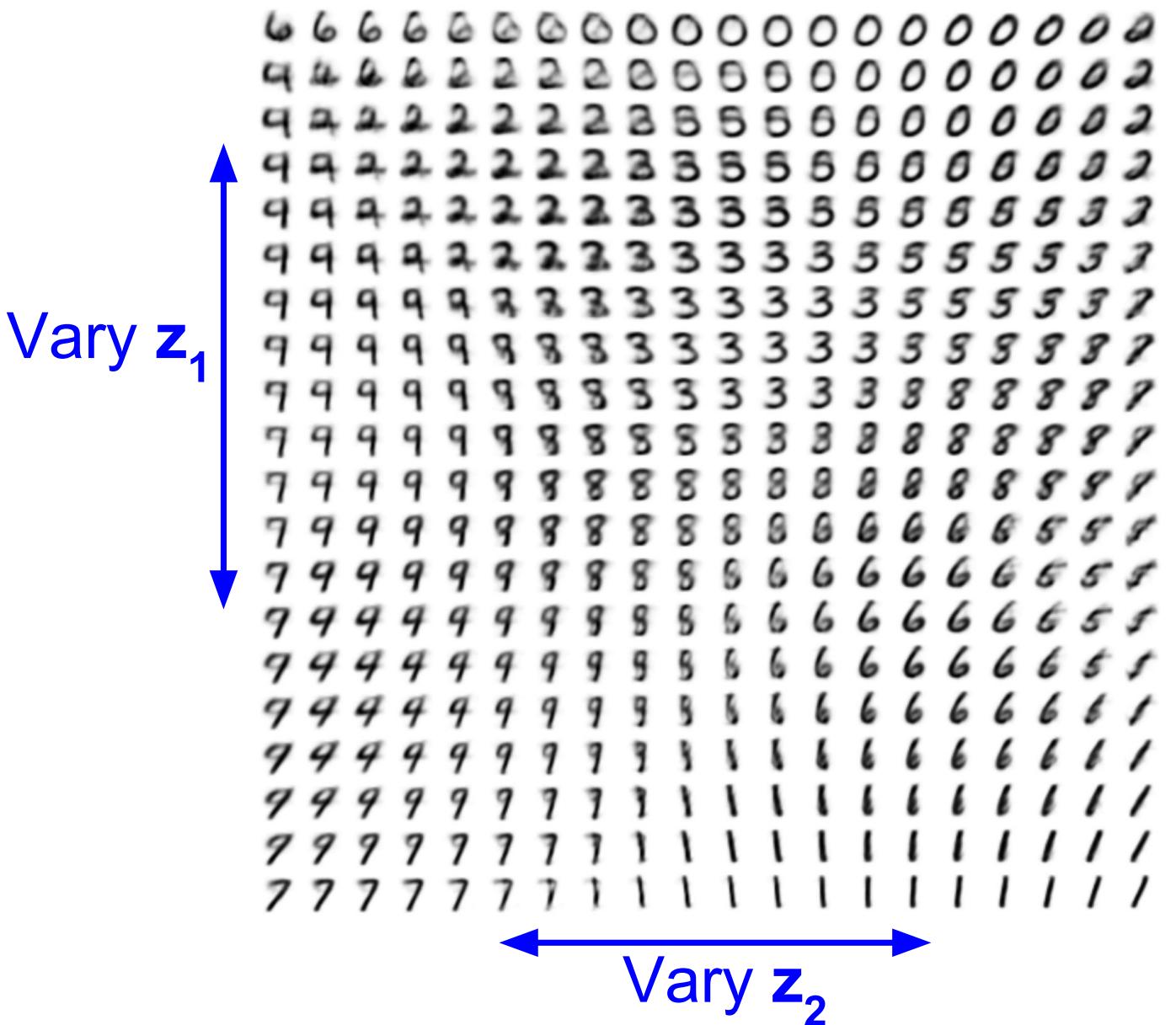


# Variational Autoencoders: Generating Data!

Use decoder network. Now sample z from prior!



Data manifold for 2-d  $z$



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

# Variational Autoencoders: Generating Data!

Diagonal prior on  $\mathbf{z}$   
=> independent  
latent variables

Different  
dimensions of  $\mathbf{z}$   
encode  
interpretable factors  
of variation

Degree of smile

Vary  $\mathbf{z}_1$



Vary  $\mathbf{z}_2$

Head pose

# Variational Autoencoders: Generating Data!

Diagonal prior on  $\mathbf{z}$   
=> independent  
latent variables

Different  
dimensions of  $\mathbf{z}$   
encode  
interpretable factors  
of variation

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



Degree of smile

Vary  $z_1$

Head pose

Vary  $z_2$

# Variational Autoencoders: Generating Data!



32x32 CIFAR-10



Labeled Faces in the Wild

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# Variational Autoencoders

Probabilistic spin to traditional autoencoders => allows generating data

Defines an intractable density => derive and optimize a (variational) lower bound

## Pros:

- Principled approach to generative models
- Allows inference of  $q(z|x)$ , can be useful feature representation for other tasks

## Cons:

- Maximizes lower bound of likelihood: okay, but not as good evaluation as PixelRNN/PixelCNN
- Samples blurrier and lower quality compared to state-of-the-art (GANs)

## Active areas of research:

- More flexible approximations, e.g. richer approximate posterior instead of diagonal Gaussian
- Incorporating structure in latent variables

# Generative Adversarial Networks (GAN)

# So far...

PixelCNNs define tractable density function, optimize likelihood of training data:

$$p_{\theta}(x) = \prod_{i=1}^n p_{\theta}(x_i|x_1, \dots, x_{i-1})$$

VAEs define intractable density function with latent  $\mathbf{z}$ :

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

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

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VAEs define intractable density function with latent  $\mathbf{z}$ :

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

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?

# So far...

PixelCNNs define tractable density function, optimize likelihood of training data:

$$p_{\theta}(x) = \prod_{i=1}^n p_{\theta}(x_i|x_1, \dots, x_{i-1})$$

VAEs define intractable density function with latent  $\mathbf{z}$ :

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

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?

# Generative Adversarial Networks

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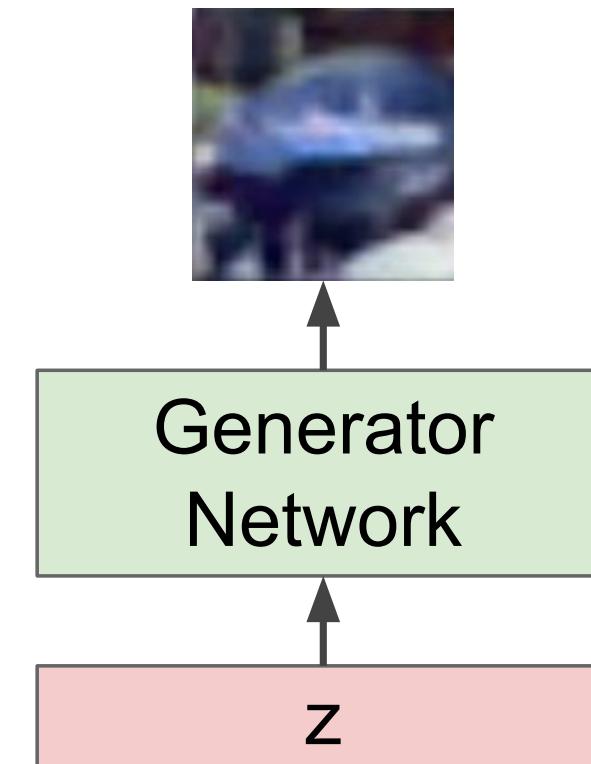
Solution: Sample from a simple distribution, e.g. random noise. Learn transformation to training distribution.

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

A: A neural network!

Output: Sample from training distribution

Input: Random noise



# 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

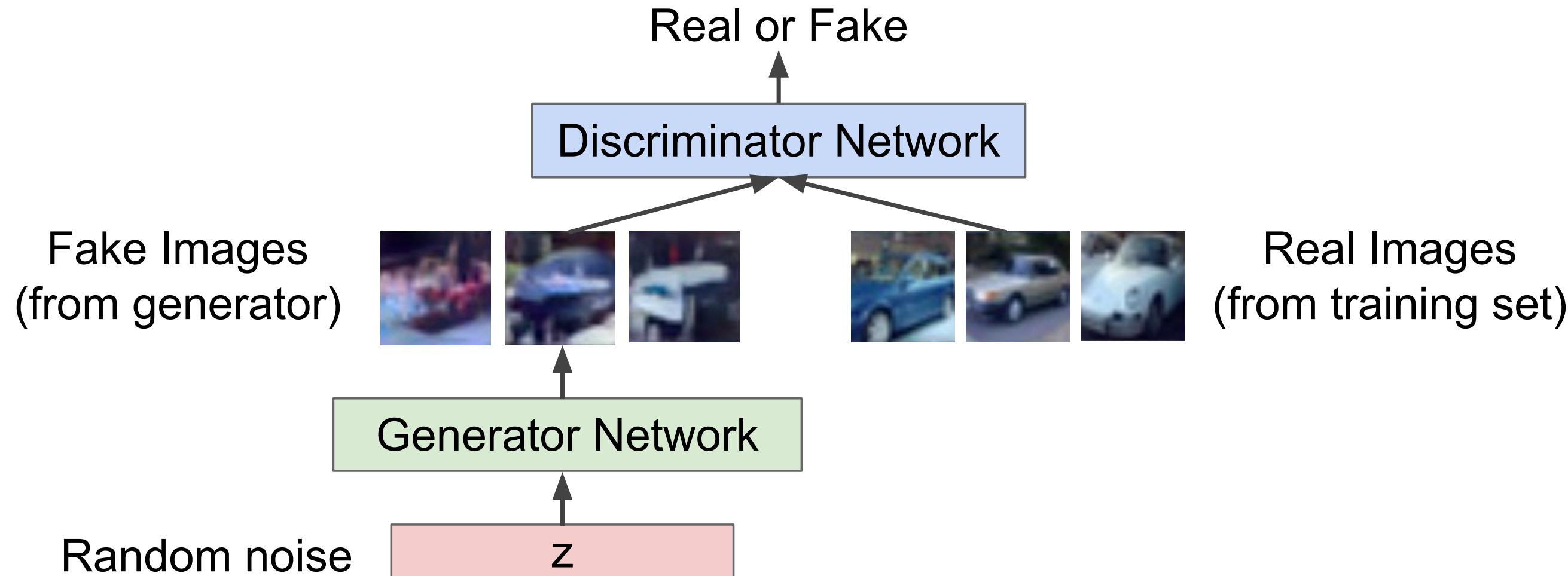
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Fake and real images copyright Emily Denton et al. 2015. Reproduced with permission.

# Training GANs: Two-player game

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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 ( $\theta_d$ ) wants to **maximize objective** such that  $D(x)$  is close to 1 (real) and  $D(G(z))$  is close to 0 (fake)
- Generator ( $\theta_g$ ) 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

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

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Alternate between:

1. **Gradient ascent** on discriminator

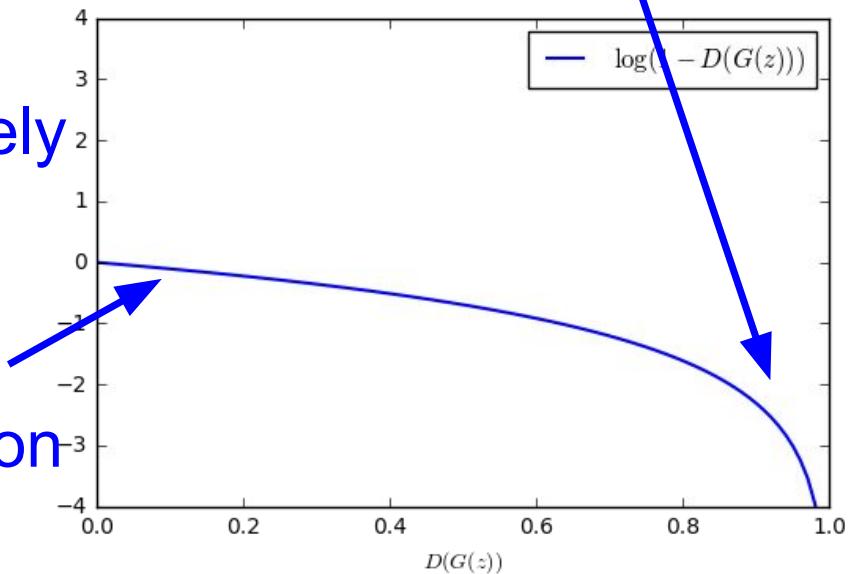
$$\max_{\theta_d} \left[ \mathbb{E}_{x \sim p_{data}} \log D_{\theta_d}(x) + \mathbb{E}_{z \sim p(z)} \log(1 - D_{\theta_d}(G_{\theta_g}(z))) \right]$$

2. **Gradient descent** on generator

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

In practice, optimizing this generator objective does not work well!

When sample is likely fake, want to learn from it to improve generator. But gradient in this region is relatively flat!



Gradient signal dominated by region where sample is already good

# Training GANs: Two-player game

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

Minimax objective function:

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

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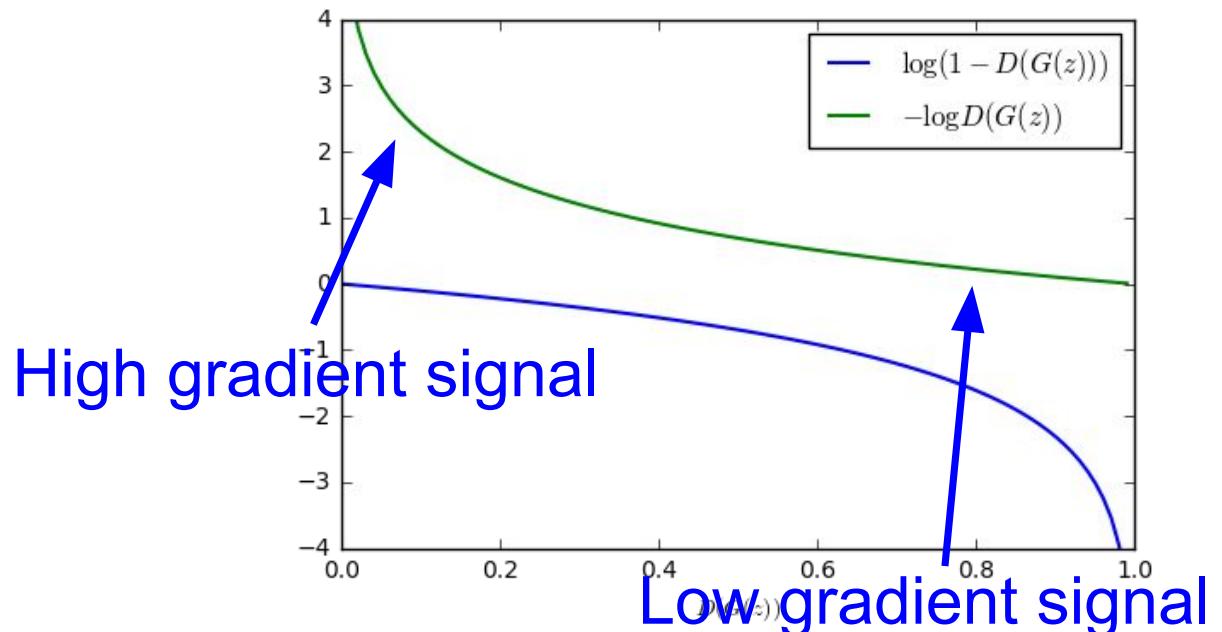
$$\max_{\theta_d} \left[ \mathbb{E}_{x \sim p_{data}} \log D_{\theta_d}(x) + \mathbb{E}_{z \sim p(z)} \log(1 - D_{\theta_d}(G_{\theta_g}(z))) \right]$$

2. Instead: **Gradient ascent** on generator, different objective

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

Instead of minimizing likelihood of discriminator being correct, now maximize likelihood of discriminator being wrong.

Same objective of fooling discriminator, but now higher gradient signal for bad samples => works much better! Standard in practice.



# 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  $\{\mathbf{z}^{(1)}, \dots, \mathbf{z}^{(m)}\}$  from noise prior  $p_g(\mathbf{z})$ .
- Sample minibatch of  $m$  examples  $\{\mathbf{x}^{(1)}, \dots, \mathbf{x}^{(m)}\}$  from data generating distribution  $p_{\text{data}}(\mathbf{x})$ .
- 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  $\{\mathbf{z}^{(1)}, \dots, \mathbf{z}^{(m)}\}$  from noise prior  $p_g(\mathbf{z})$ .

- 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

## Putting it together: GAN training algorithm

```
for number of training iterations do
    for k steps do
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        • Sample minibatch of  $m$  examples  $\{\mathbf{x}^{(1)}, \dots, \mathbf{x}^{(m)}\}$  from data generating distribution  $p_{\text{data}}(\mathbf{x})$ .
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    end for
    • Sample minibatch of  $m$  noise samples  $\{\mathbf{z}^{(1)}, \dots, \mathbf{z}^{(m)}\}$  from noise prior  $p_g(\mathbf{z})$ .
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$$\nabla_{\theta_g} \frac{1}{m} \sum_{i=1}^m \log(D_{\theta_d}(G_{\theta_g}(\mathbf{z}^{(i)})))$$

end for
```

Some find  $k=1$  more stable, others use  $k > 1$ , no best rule.

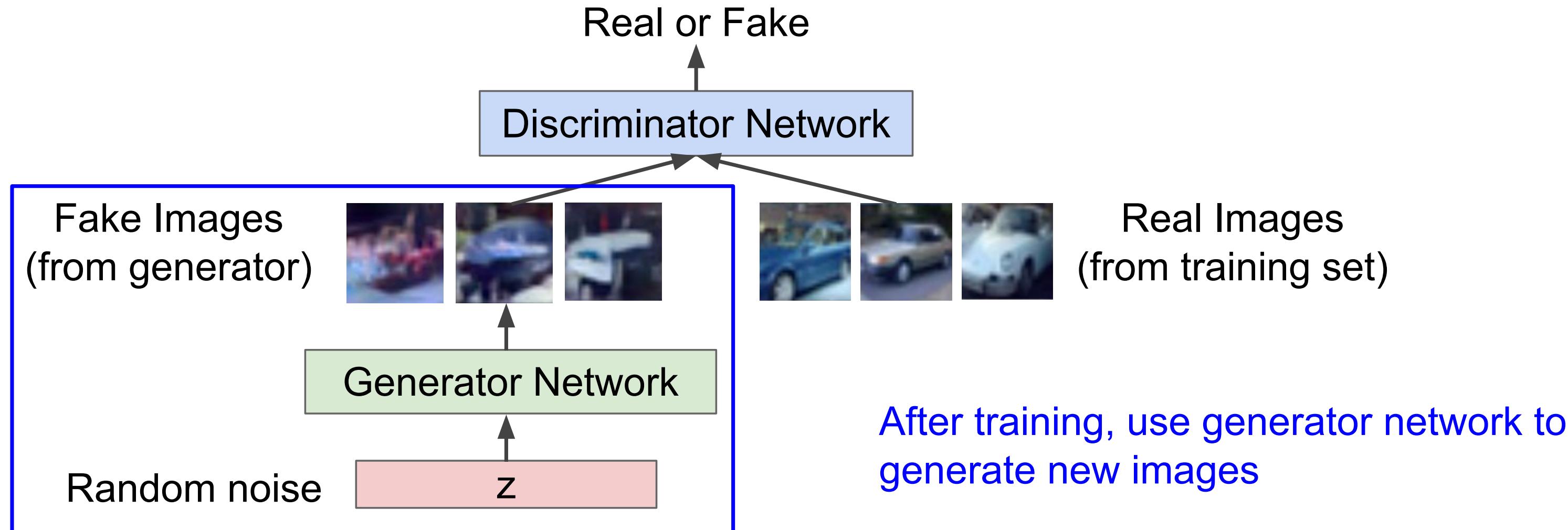
Recent work (e.g. Wasserstein GAN) alleviates this problem, better stability!

# 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

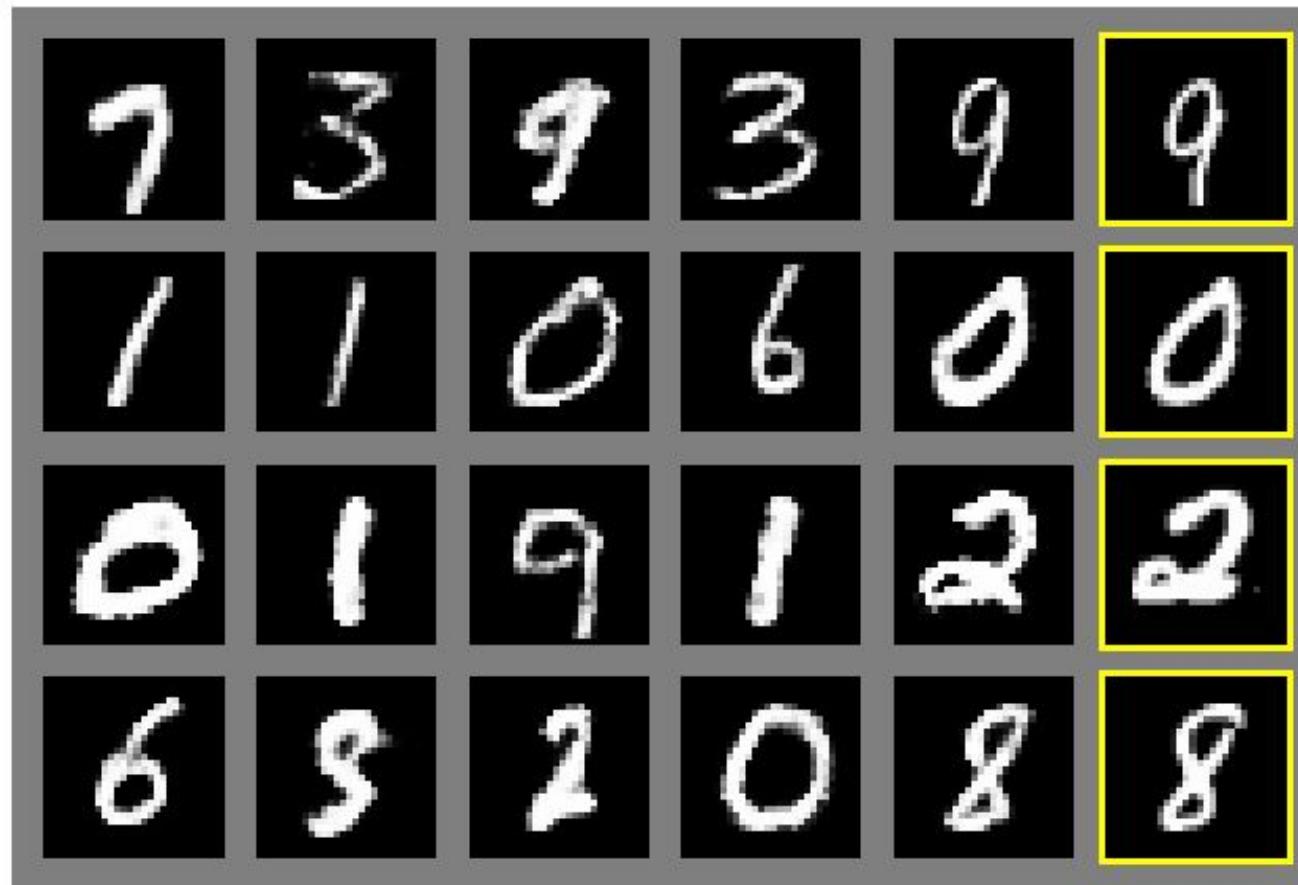
**Discriminator network:** try to distinguish between real and fake images



Fake and real images copyright Emily Denton et al. 2015. Reproduced with permission.

# Generative Adversarial Nets

Generated samples



Nearest neighbor from training set

Figures copyright Ian Goodfellow et al., 2014. Reproduced with permission.

# Generative Adversarial Nets

Generated samples (CIFAR-10)



Nearest neighbor from training set

Figures copyright Ian Goodfellow et al., 2014. Reproduced with permission.

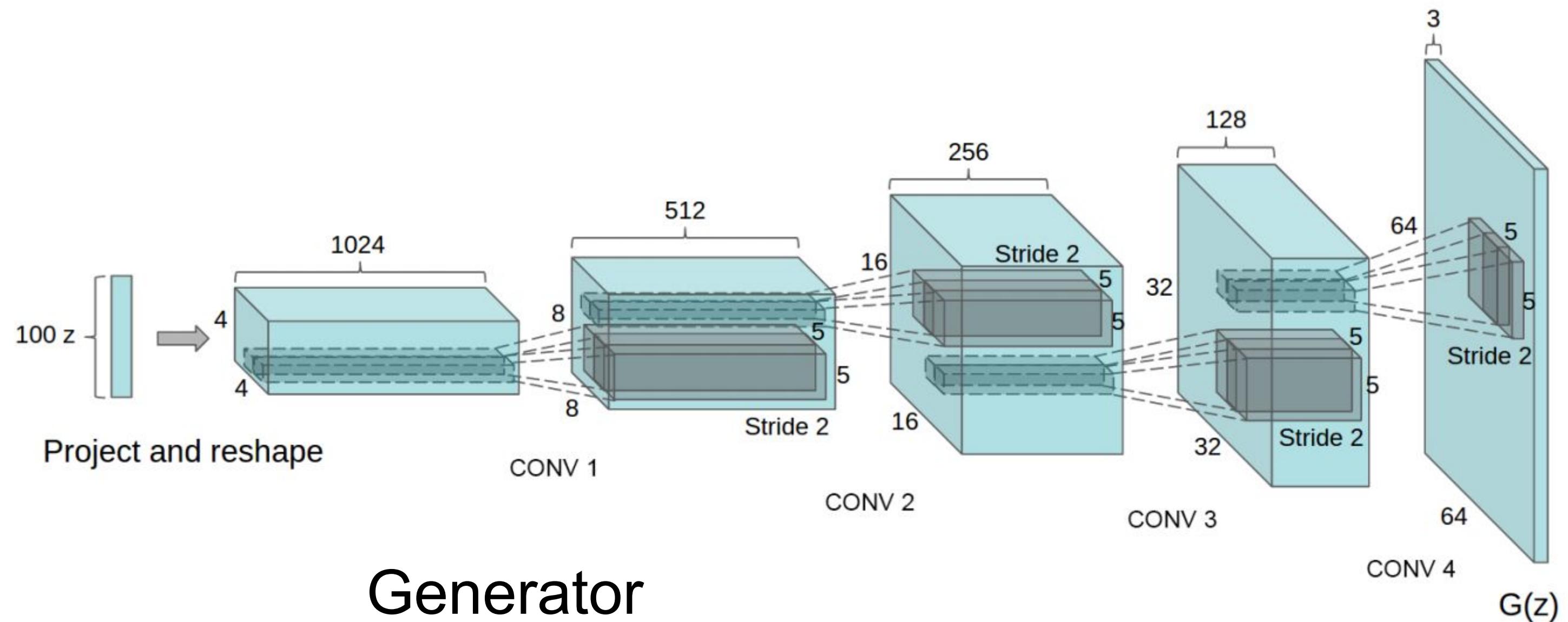
# Generative Adversarial Nets: Convolutional Architectures

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.

# Generative Adversarial Nets: Convolutional Architectures



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

# Generative Adversarial Nets: Convolutional Architectures

Samples  
from the  
model look  
much  
better!



Radford et al,  
ICLR 2016

# Generative Adversarial Nets: Convolutional Architectures

Interpolating  
between  
random  
points in latent  
space



Radford et al,  
ICLR 2016

# Generative Adversarial Nets: Interpretable Vector Math

Smiling woman   Neutral woman   Neutral man

Samples  
from the  
model



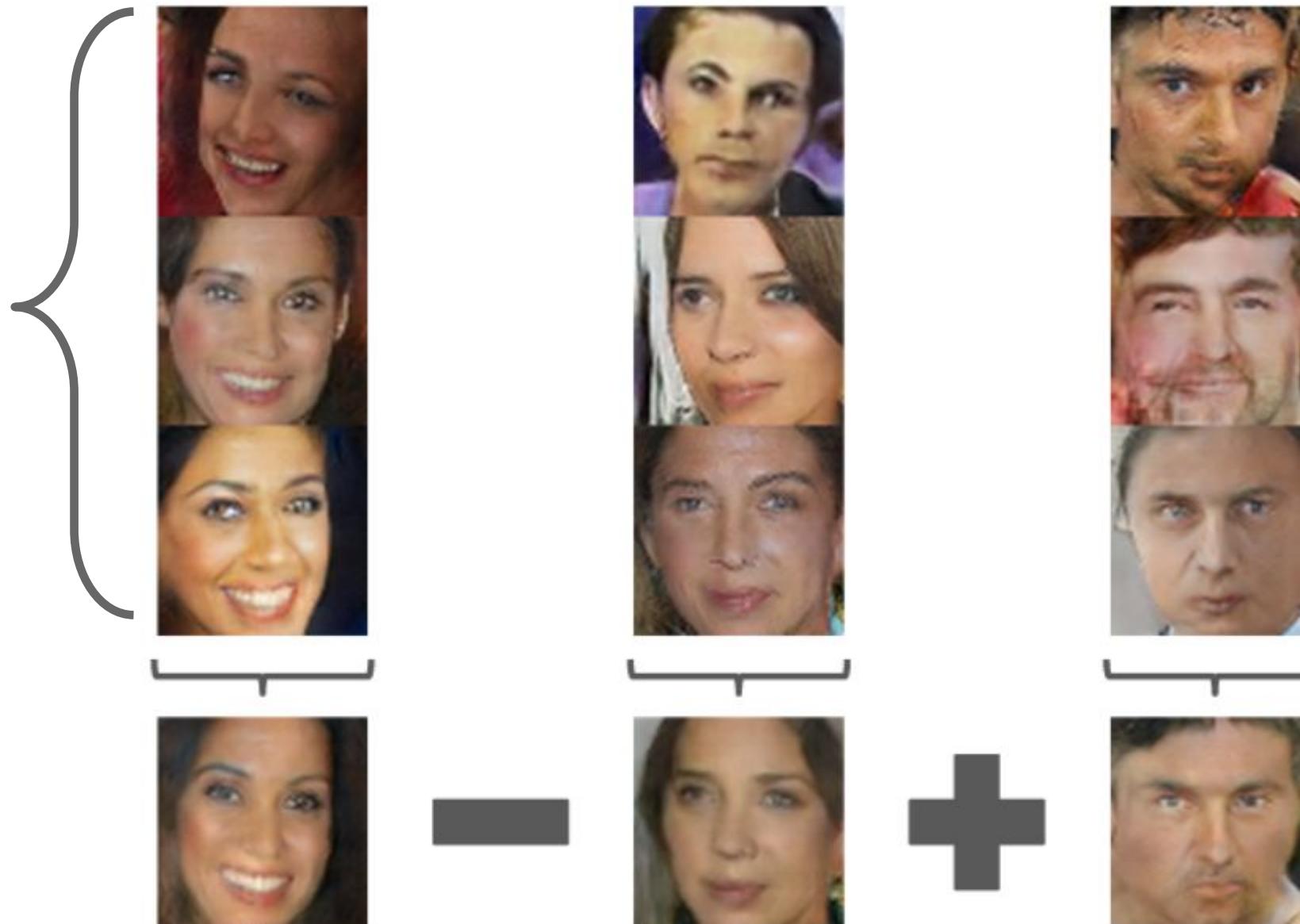
Radford et al, ICLR 2016

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Radford et al, ICLR 2016

Smiling woman   Neutral woman   Neutral man

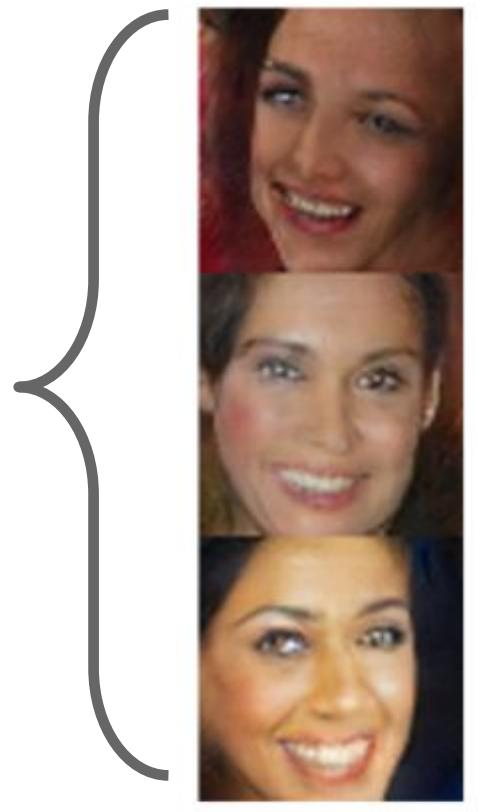
Samples  
from the  
model



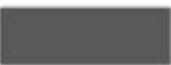
# Generative Adversarial Nets: Interpretable Vector Math

Smiling woman   Neutral woman   Neutral man

Samples  
from the  
model



Average Z  
vectors, do  
arithmetic



Radford et al, ICLR 2016

# Generative Adversarial Nets: Interpretable Vector Math

Glasses man



Radford et al,  
ICLR 2016

No glasses man



No glasses woman



# Generative Adversarial Nets: Interpretable Vector Math

Glasses man



No glasses man

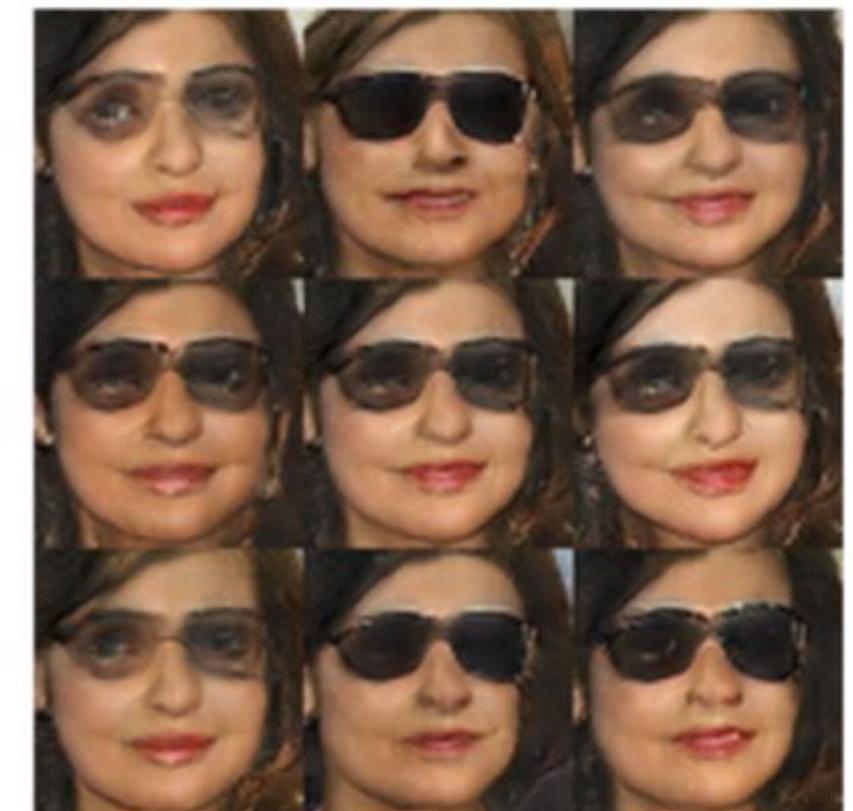


No glasses woman



Radford et al,  
ICLR 2016

Woman with glasses



# 2017: Explosion of GANs

## “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 Categorical 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>

# 2017: Explosion of GANs

## “The GAN Zoo”

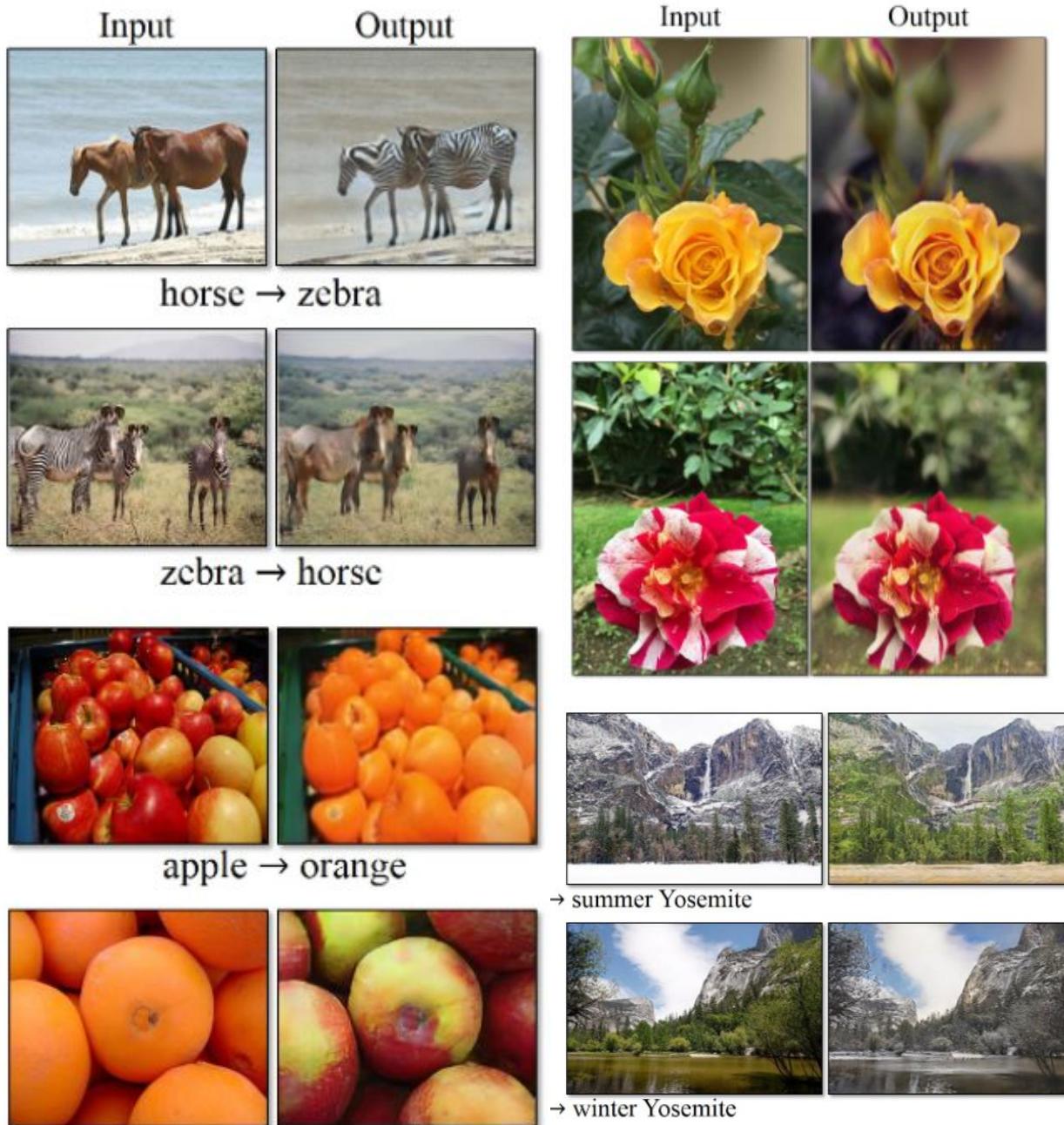
See also: <https://github.com/soumith/ganhacks> for tips and tricks for trainings GANs

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

# 2017: Explosion of GANs

Source->Target domain transfer



CycleGAN. Zhu et al. 2017.

## Text -> Image Synthesis

this small bird has a pink breast and crown, and black primaries and secondaries.

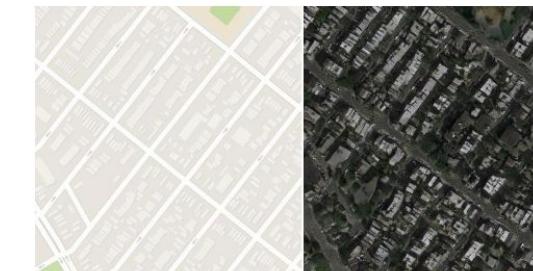


this magnificent fellow is almost all black with a red crest, and white cheek patch.



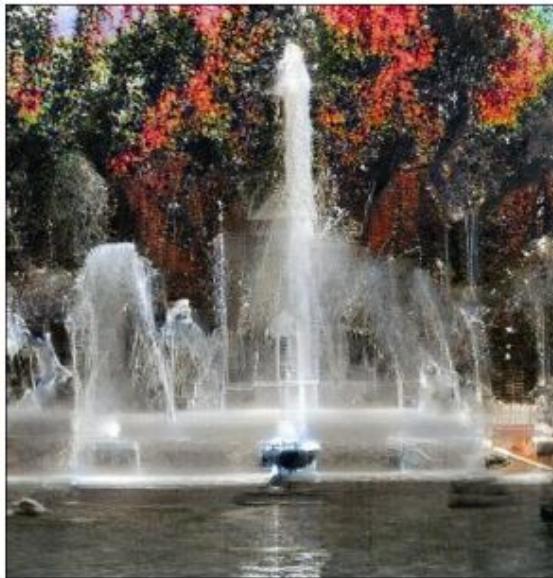
Reed et al. 2017.

Many GAN applications



Pix2pix. Isola 2017. Many examples at <https://phillipi.github.io/pix2pix/>

# 2019: BigGAN

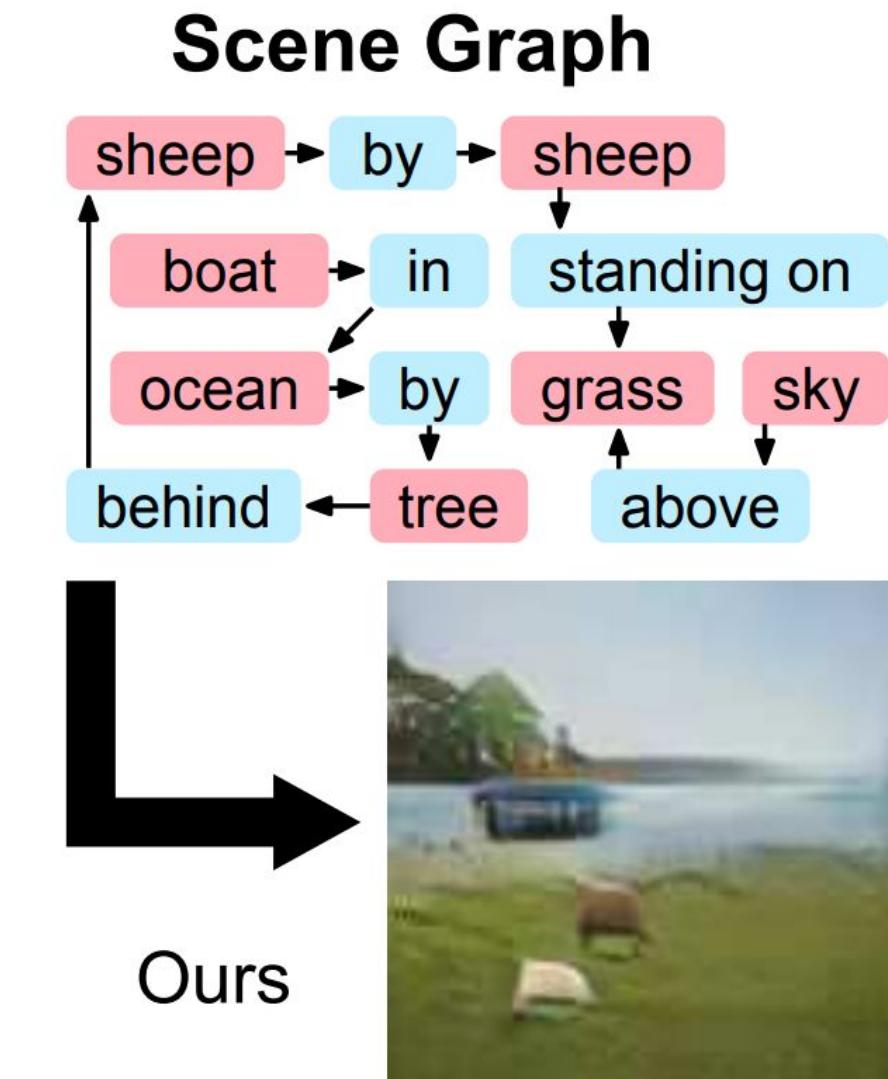


Brock et al., 2019

# Scene graphs to GANs

Specifying exactly what kind of image you want to generate.

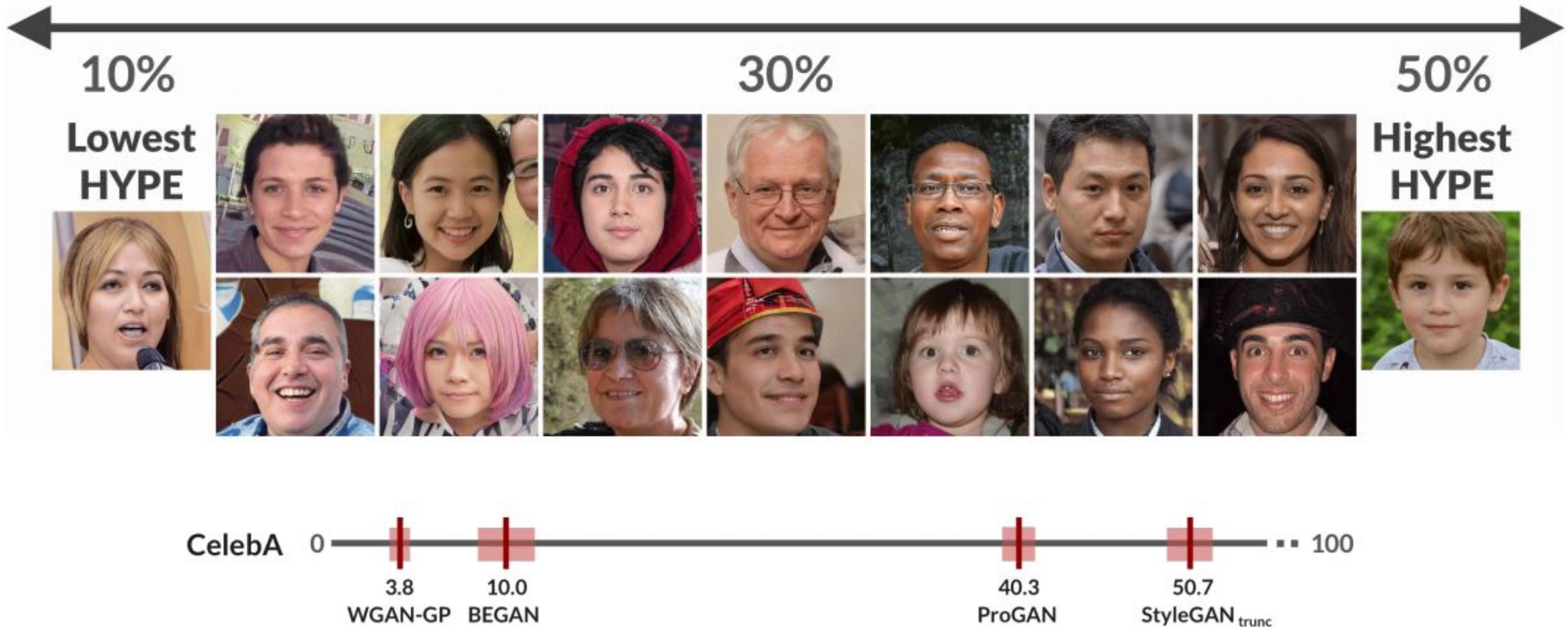
The explicit structure in scene graphs provides better image generation for complex scenes.



Figures copyright 2019. Reproduced with permission.

# HYPE: Human eYe Perceptual Evaluations

[hype.stanford.edu](https://hype.stanford.edu)



# 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:

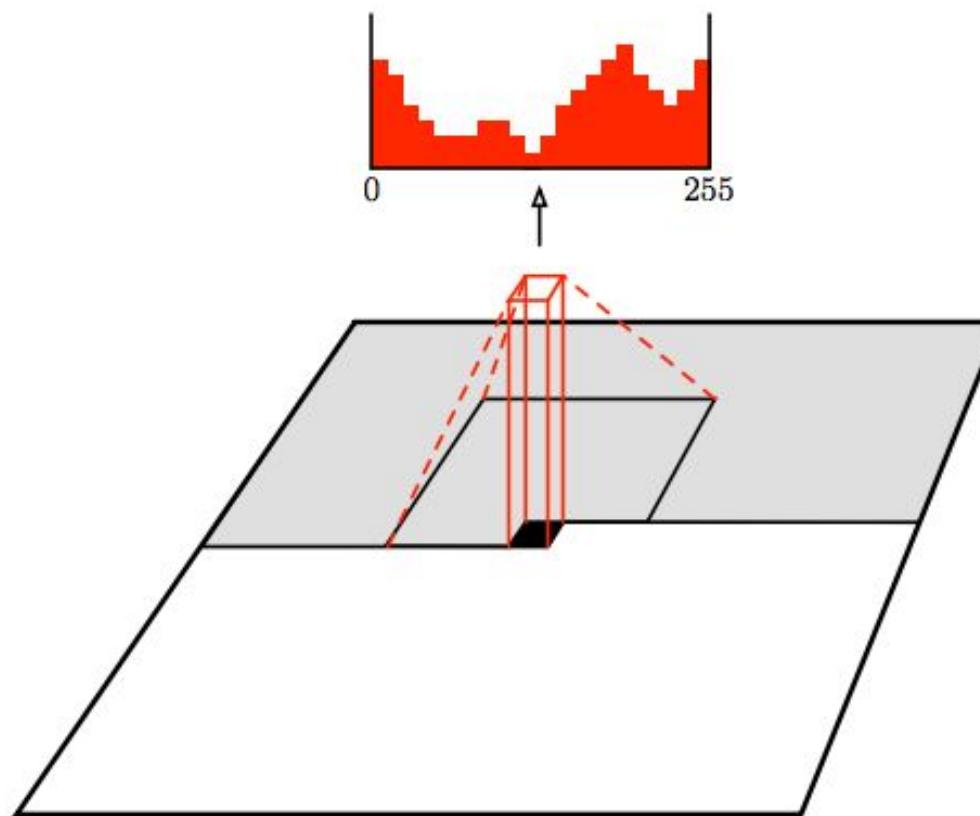
- Trickier / more unstable to train
- Can't solve inference queries such as  $p(x)$ ,  $p(z|x)$

Active areas of research:

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

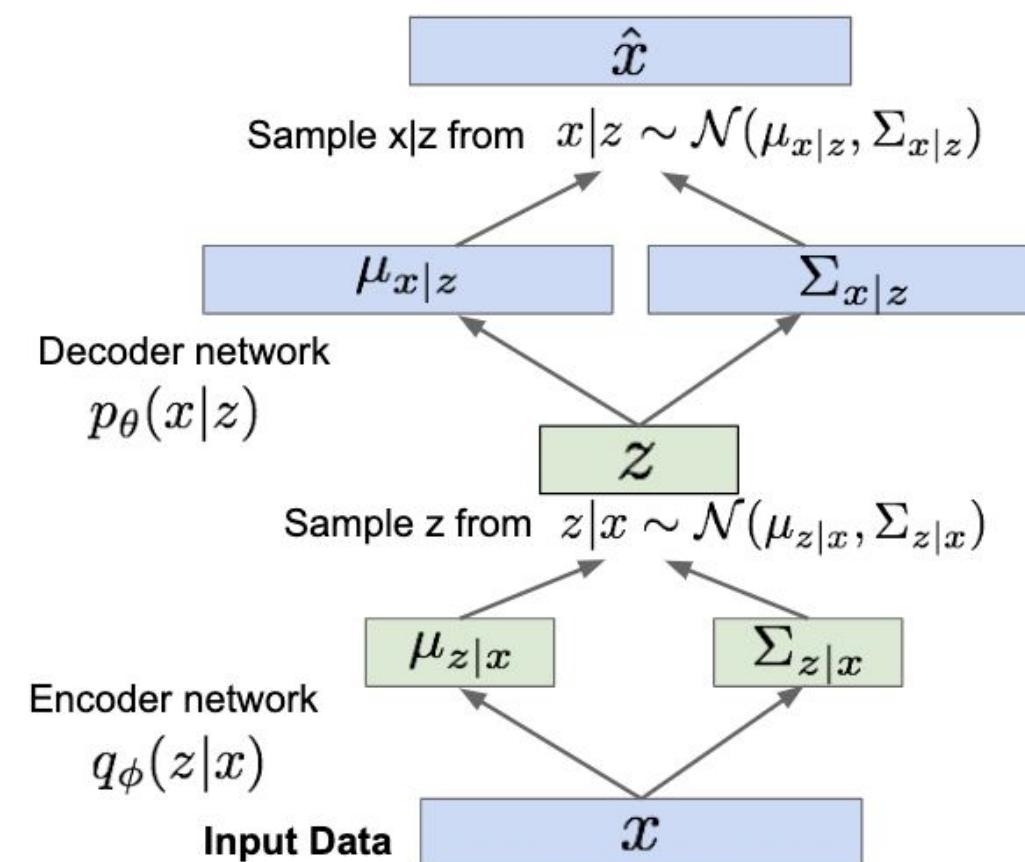
# Summary

## Autoregressive models: PixelRNN, PixelCNN



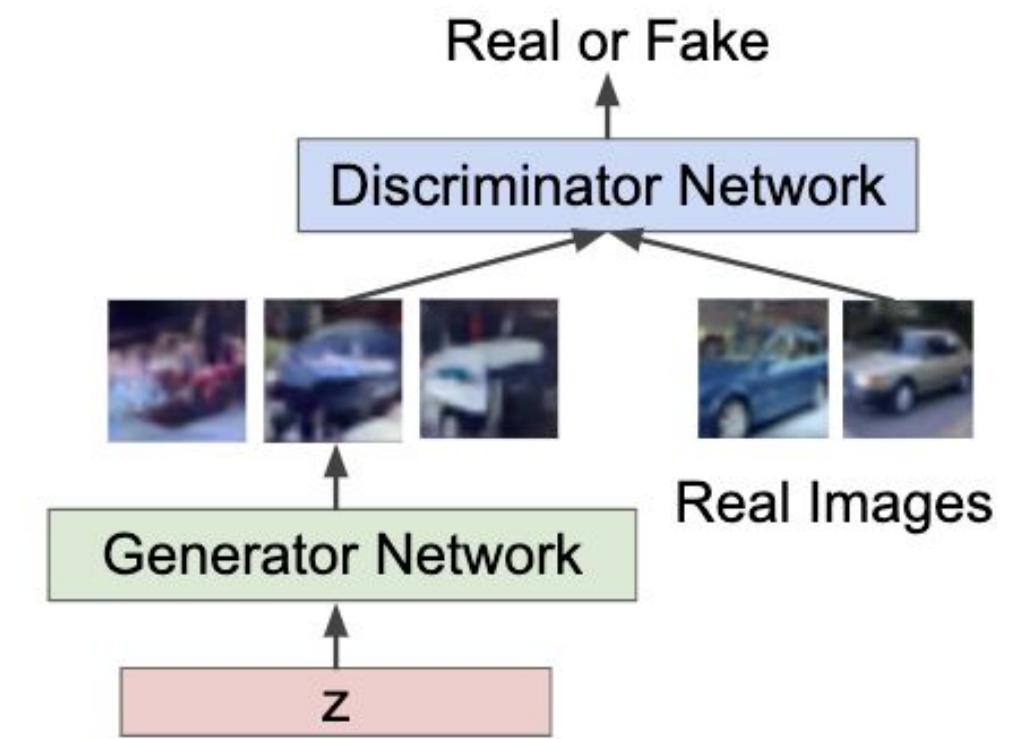
Van der Oord et al, “Conditional image generation with pixelCNN decoders”, NIPS 2016

## Variational Autoencoders



Kingma and Welling, “Auto-encoding variational bayes”, ICLR 2013

## Generative Adversarial Networks (GANs)



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