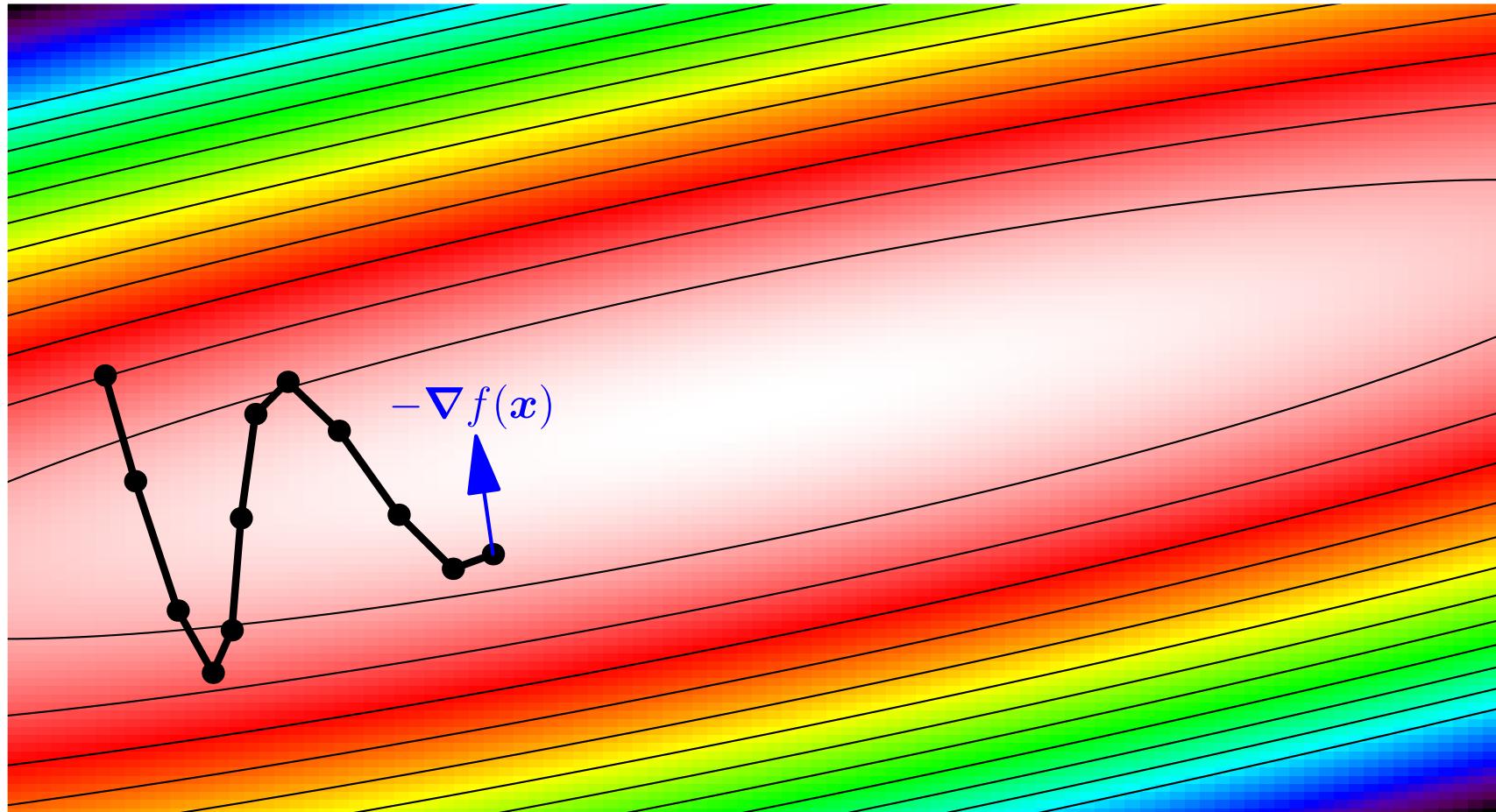


# Advanced Machine Learning

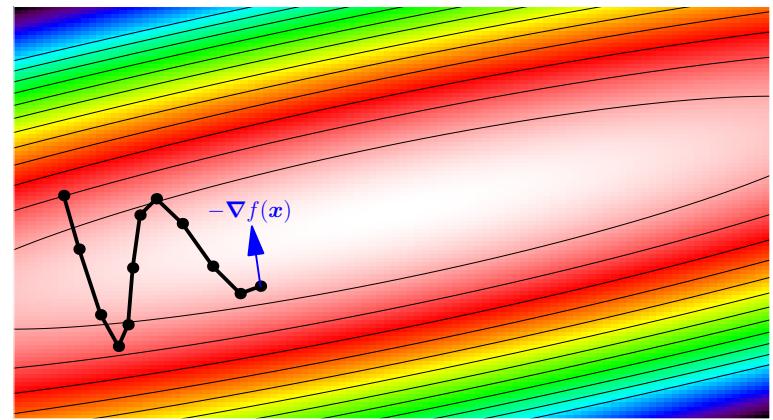
## *Stochastic Gradient Descent*



*SGD, momentum, step size, ADAM*

# Outline

1. SGD
2. Momentum
3. Loss Landscapes



# The Next Step

- In most machine learning problems we design a network and a loss function
- The rest requires simple optimisation
- Although Newton and Quasi-Newton methods ensure rapid convergence for many tasks this apparent advantage is delusional
- Since the raise of deep learning, gradient descent and its variants have become dominant

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- Rather than computing the gradient of the loss function, e.g.

$$\nabla L_{\mathcal{D}}(\mathbf{w}) = \nabla \sum_{(\mathbf{x},y) \in \mathcal{D}} L(f(\mathbf{x}|\mathbf{w}), y)^2$$

- We often compute an approximation

$$\nabla L_{\mathcal{B}}(\mathbf{w}) = \nabla \sum_{(\mathbf{x},y) \in \mathcal{B}} L(f(\mathbf{x}|\mathbf{w}), y)^2$$

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- For gradient descent we need to compute the gradient
- For most of my life this was just a pain
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# Convergence

- Asymptotic convergence of gradient descent (and SGD) is slower than quasi-Newton methods
- But there are three reasons why we don't really care
  - ★ For complex models we spend a lot of time before we are close to a quadratic minima where asymptotic convergence kicks in
  - ★ These days we often use ReLUs (rectified linear units) which are non-analytic. The convergence we discussed depends on a Taylor expansion that assumes analyticity
  - ★ We want to minimise the generalisation error, but are only minimising a poor surrogate, namely the training error

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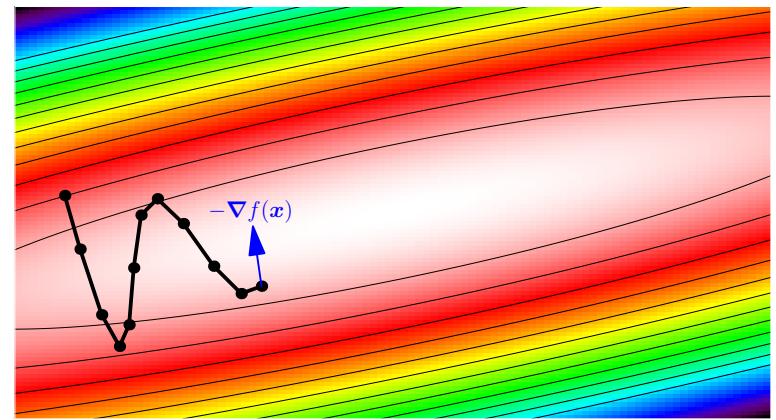
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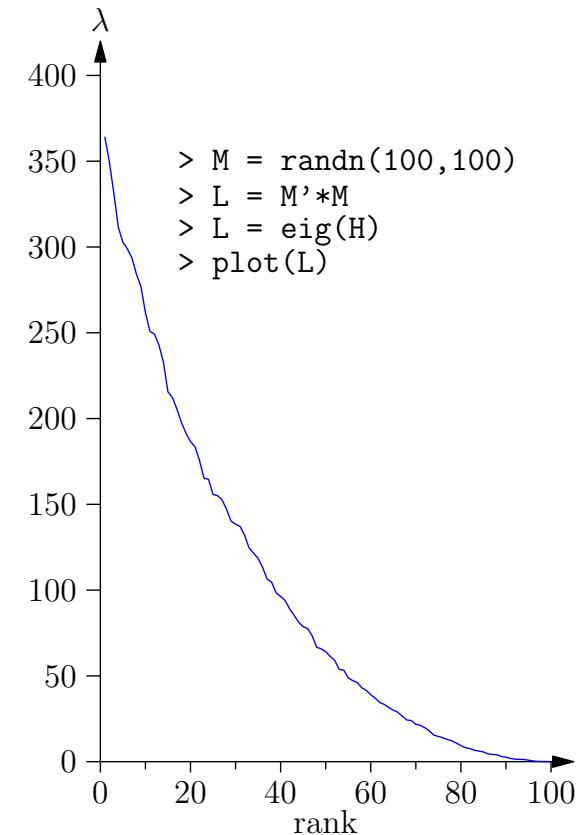


# Step Size

- The optimal step size depends on the gradient and the curvature (second derivative)
- For a quadratic minima the minimum is given by

$$x^* = x - \frac{f'(x)}{f''(x)}, \quad x^* = x - H^{-1} \nabla f(x)$$

- In high dimensions the Hessian  $H$  will have a spectrum of eigenvalues
- This means there are different scales

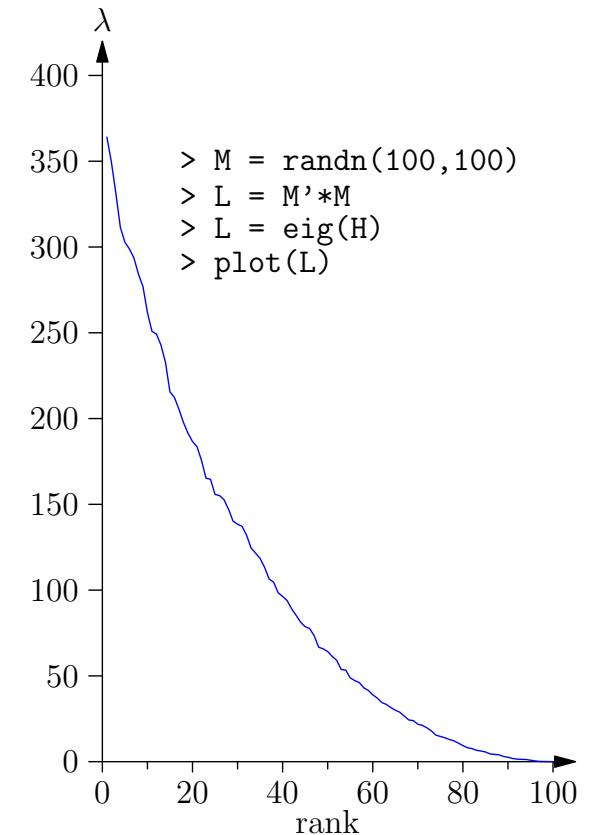


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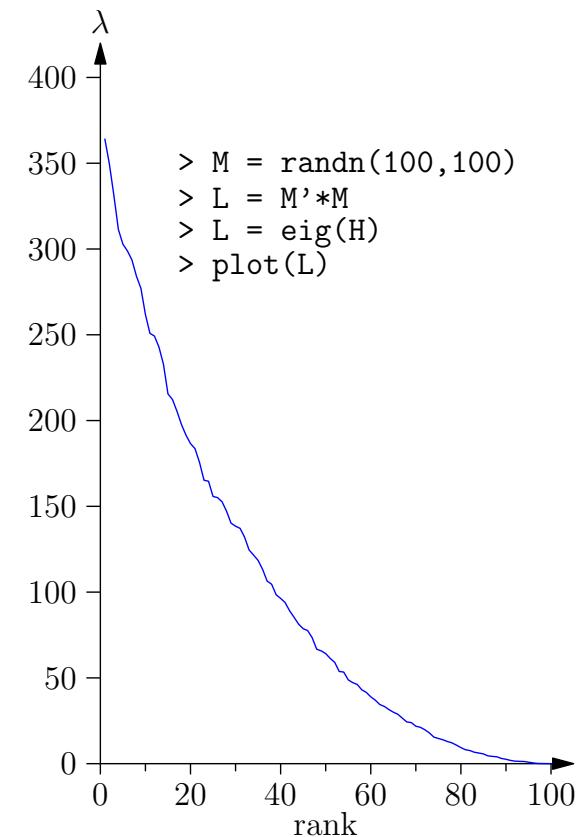


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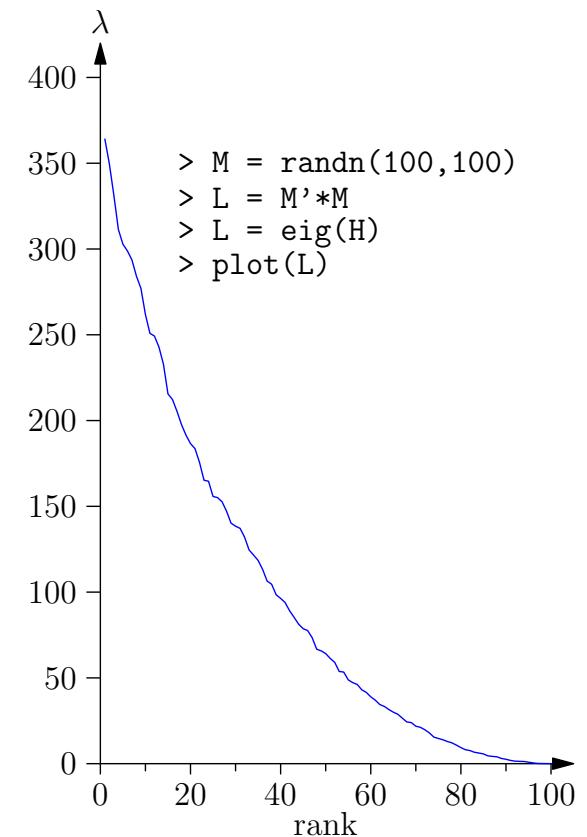


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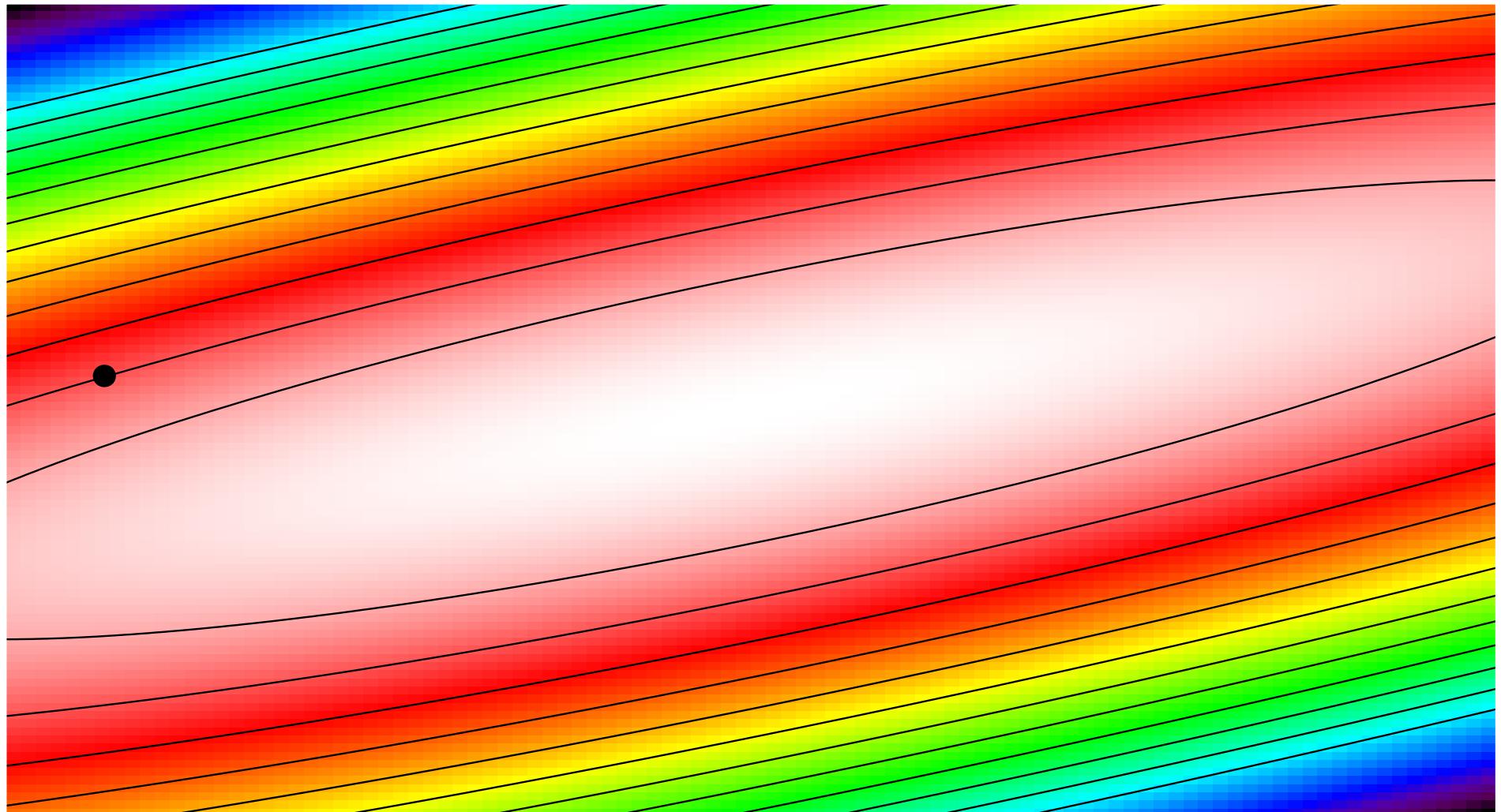
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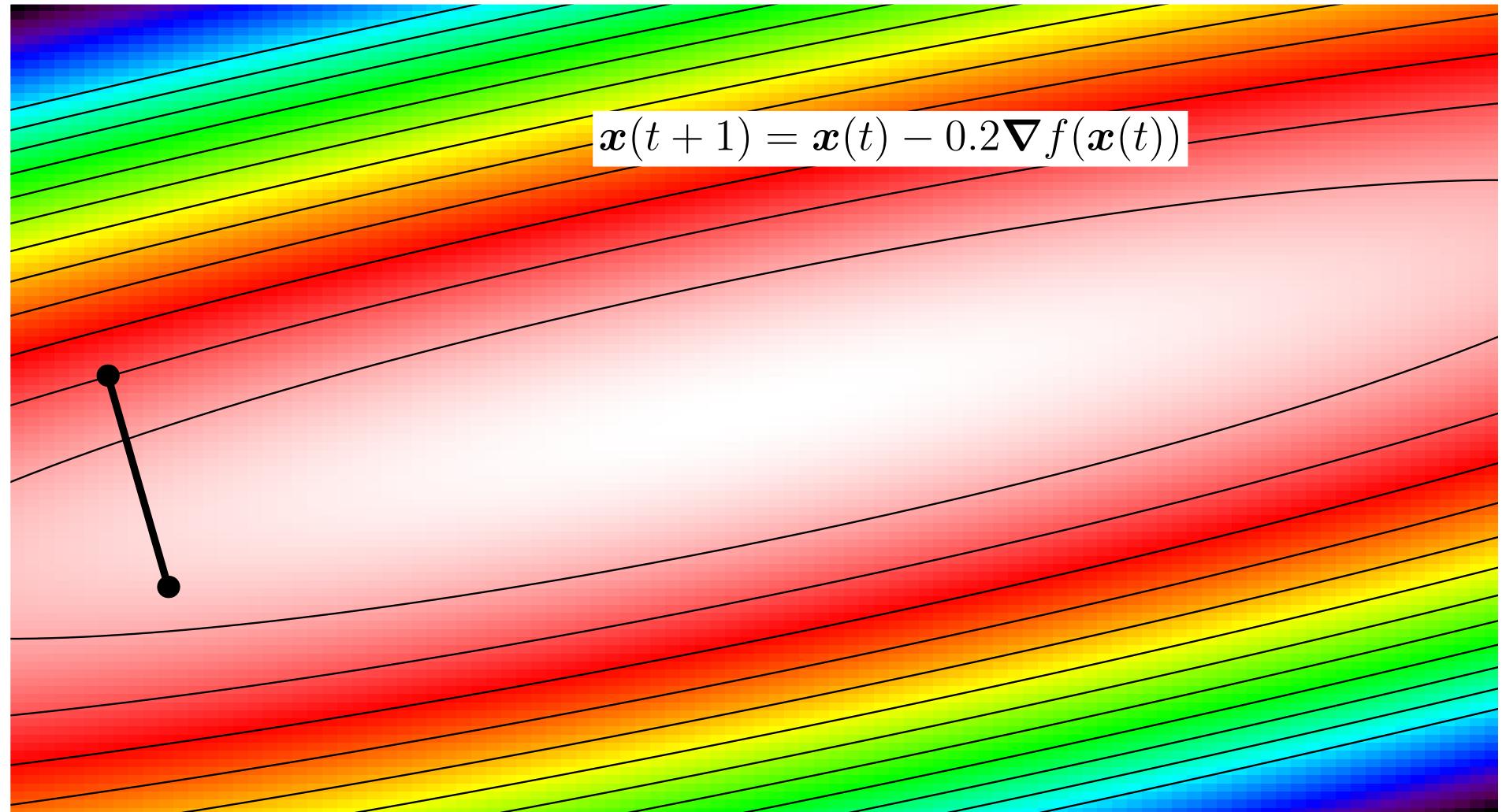
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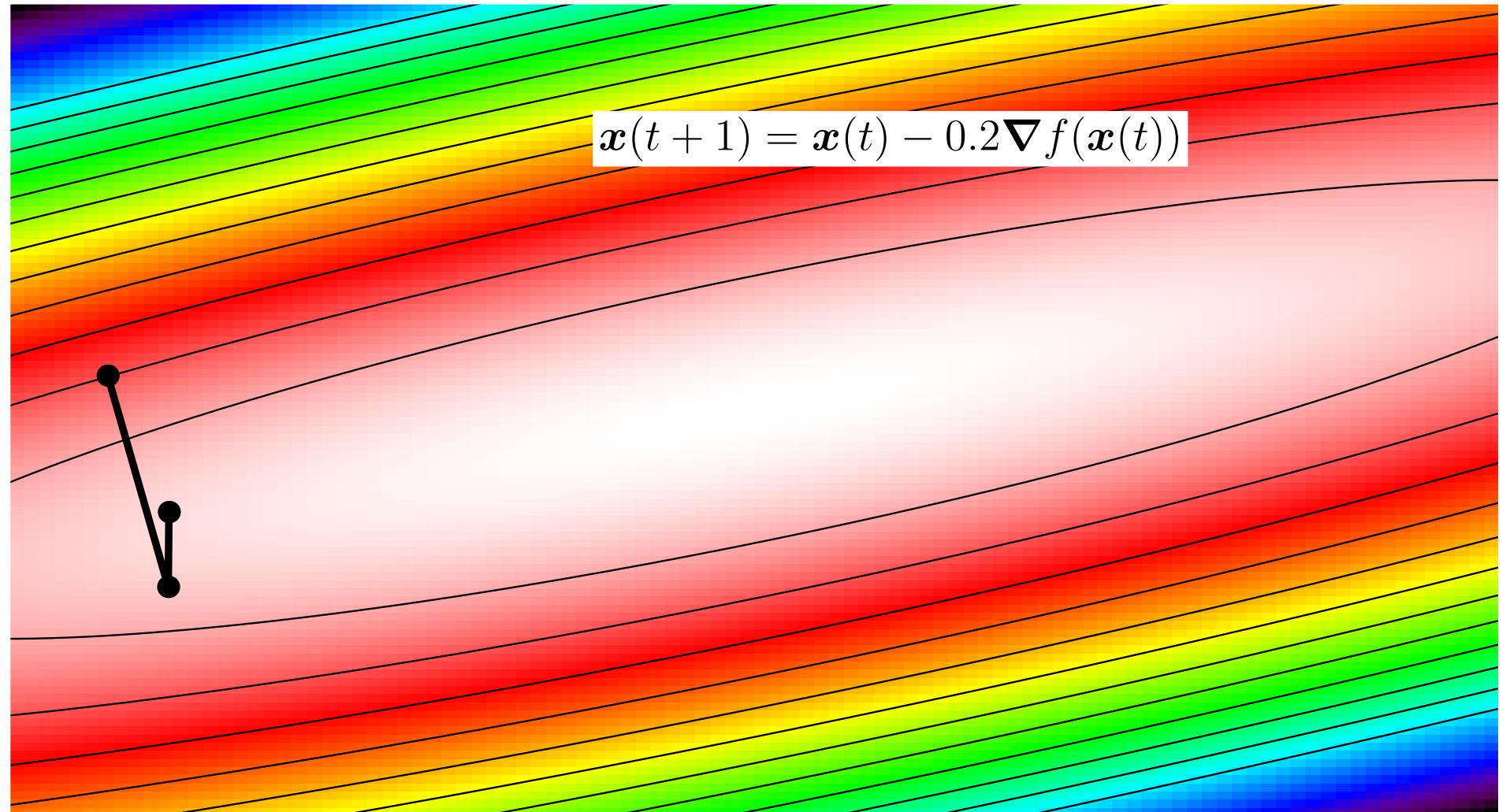
# Gradient Descent



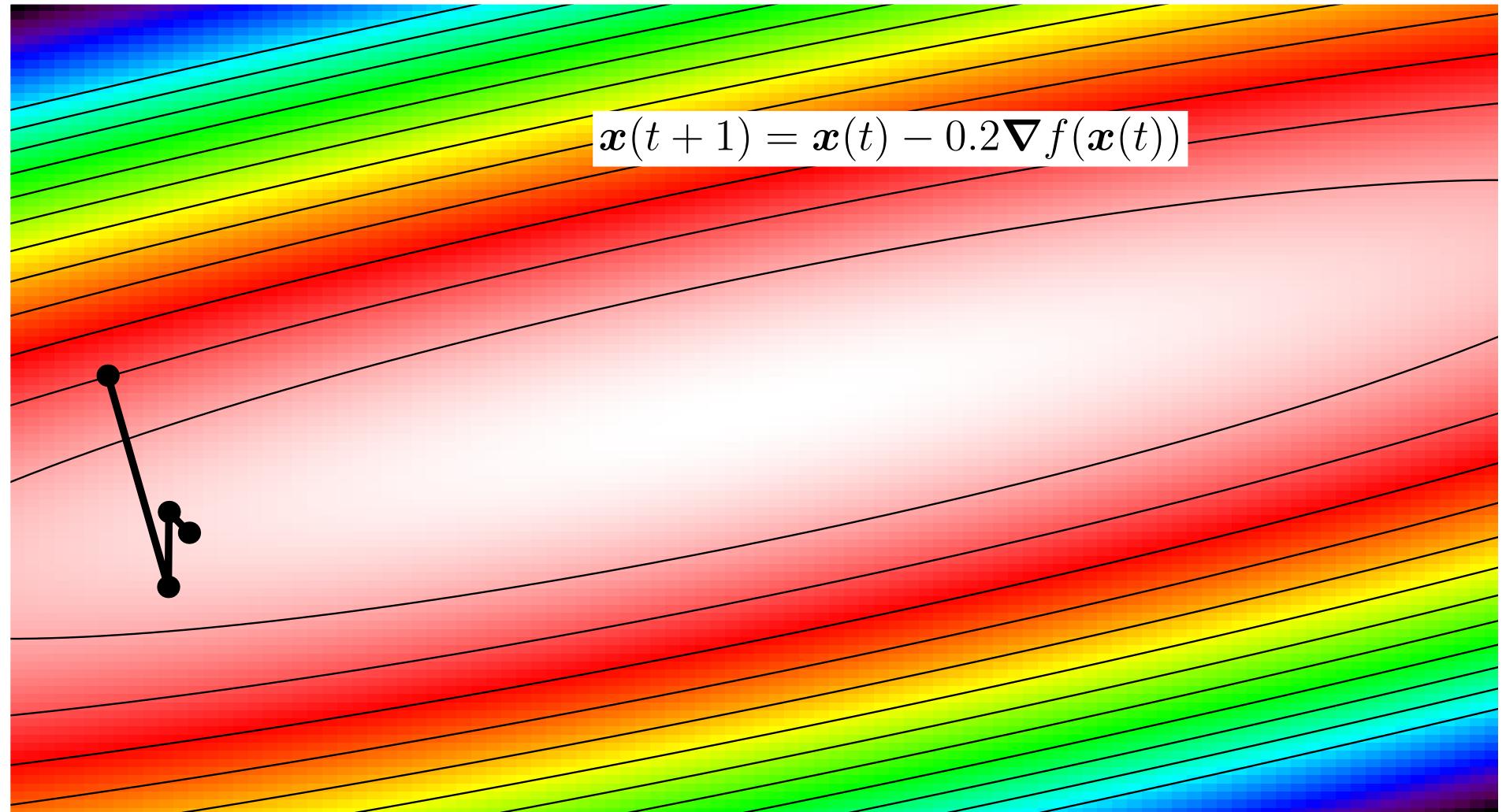
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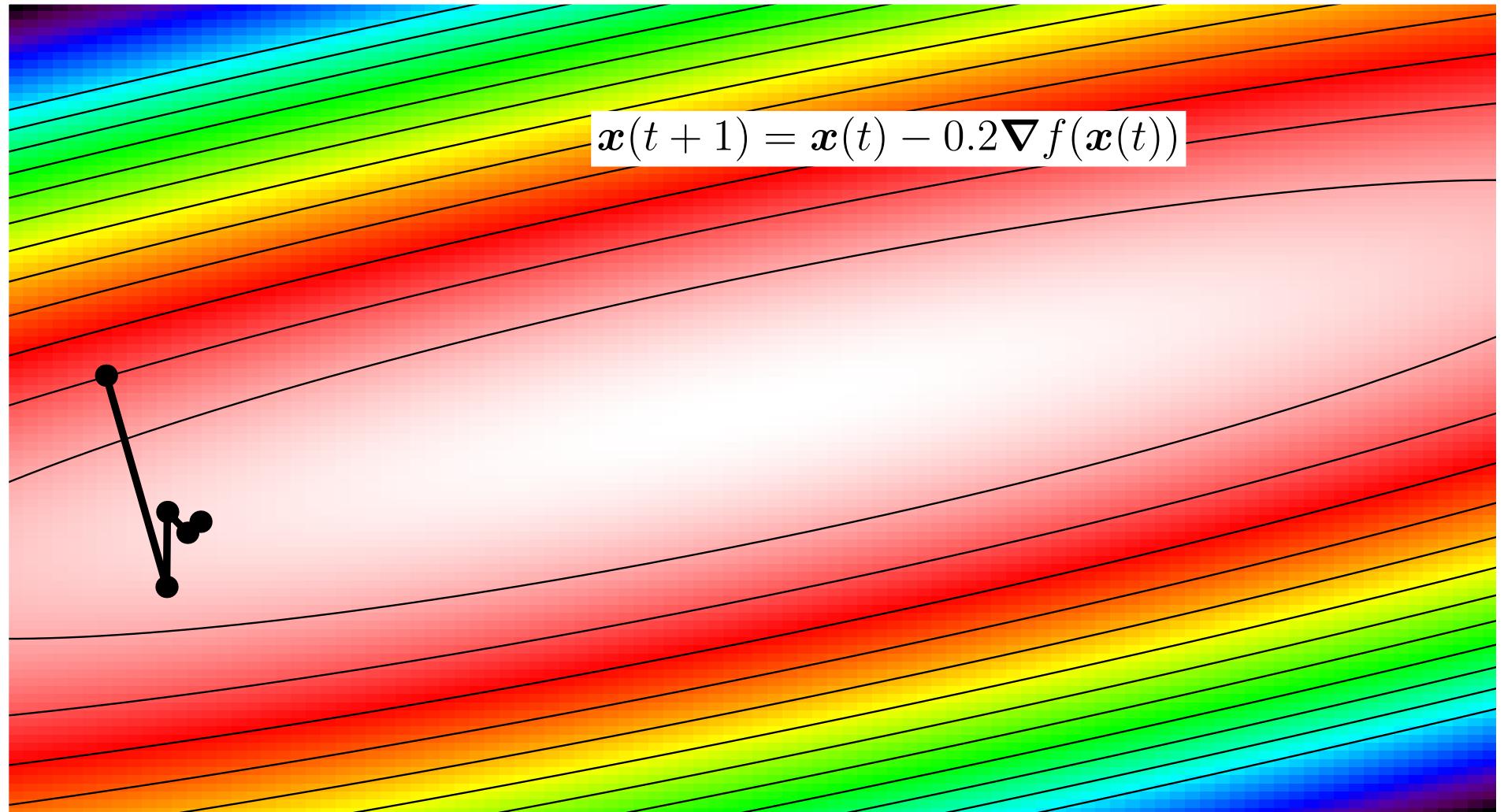
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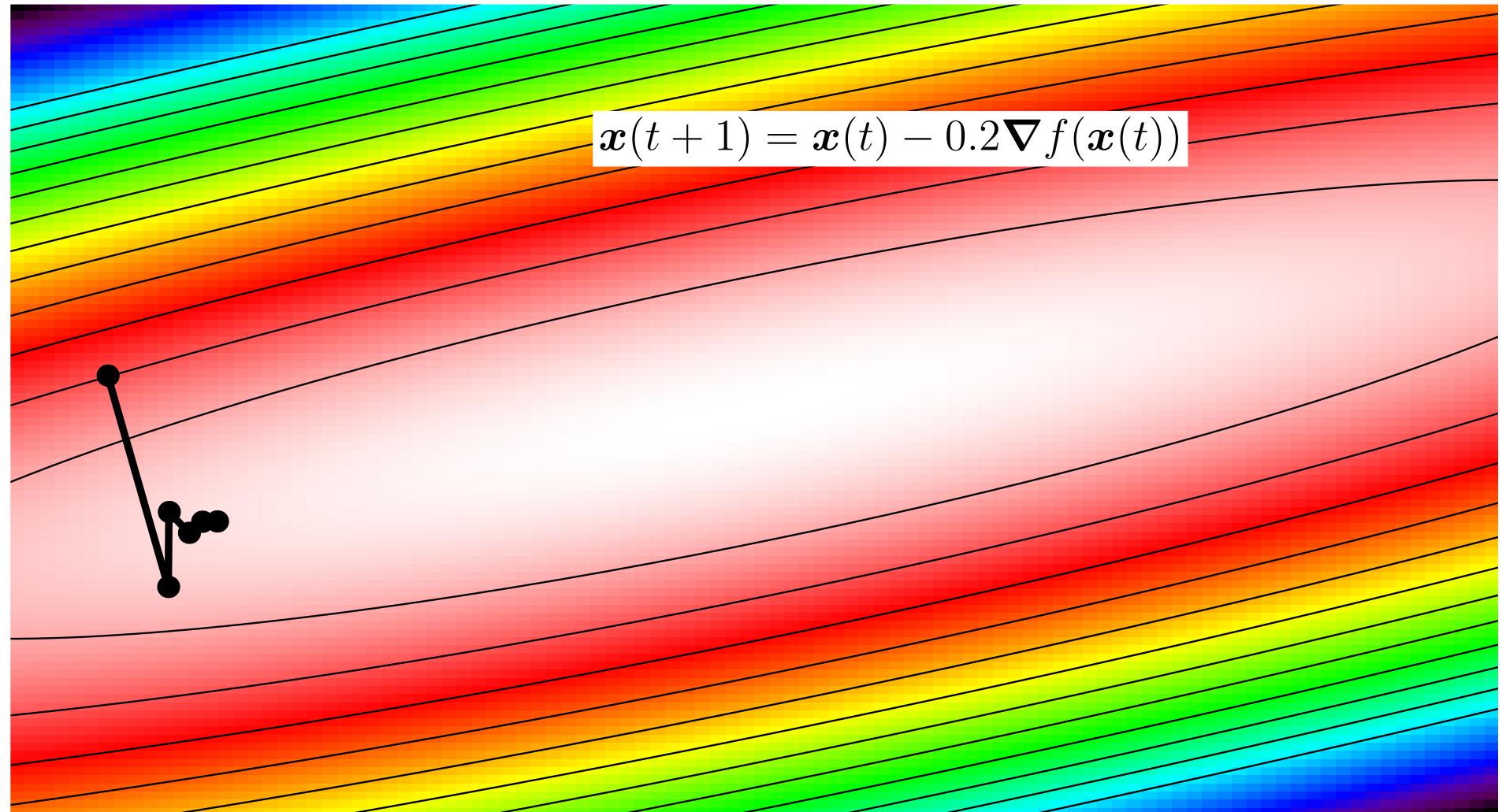
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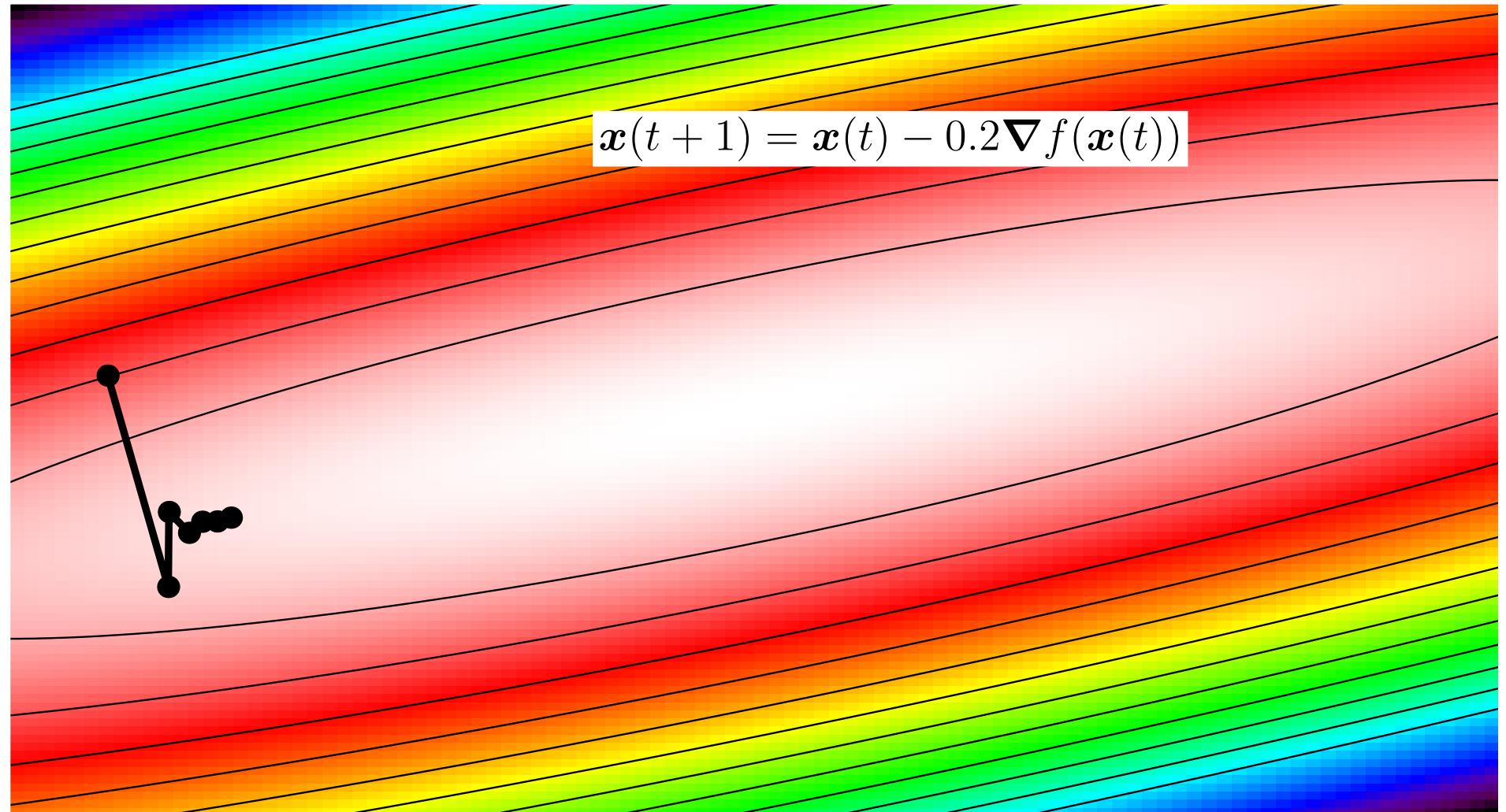
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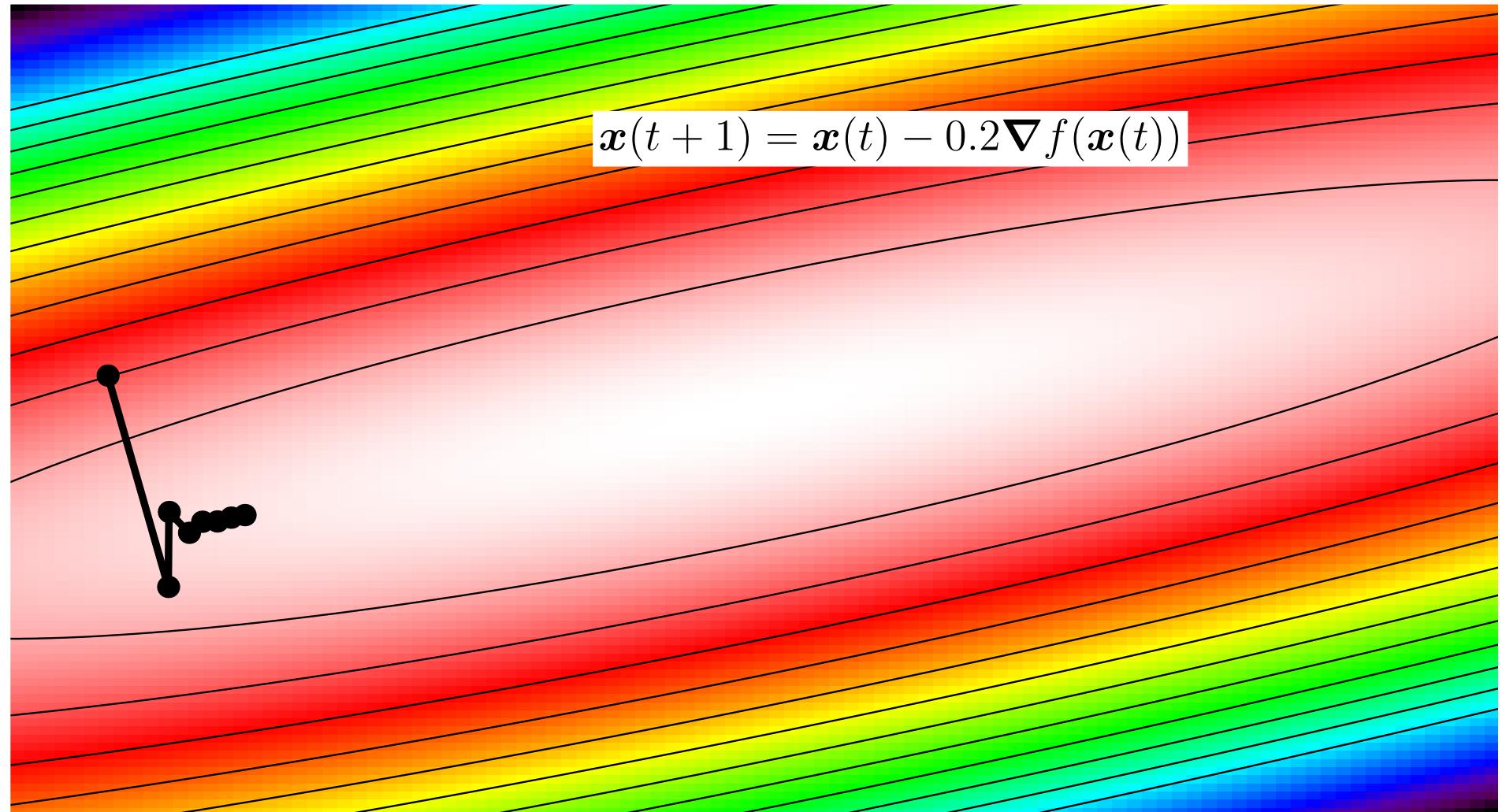
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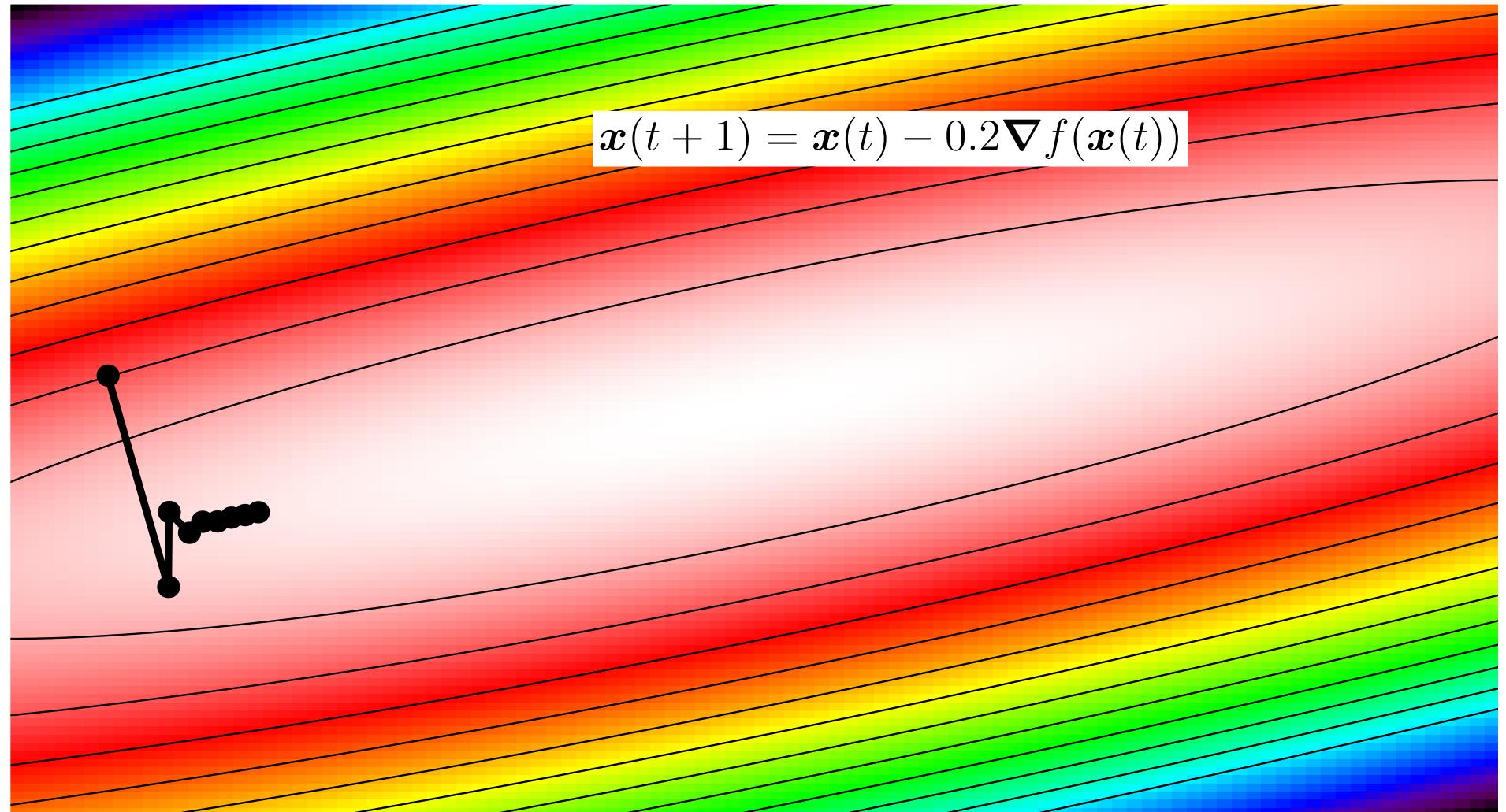
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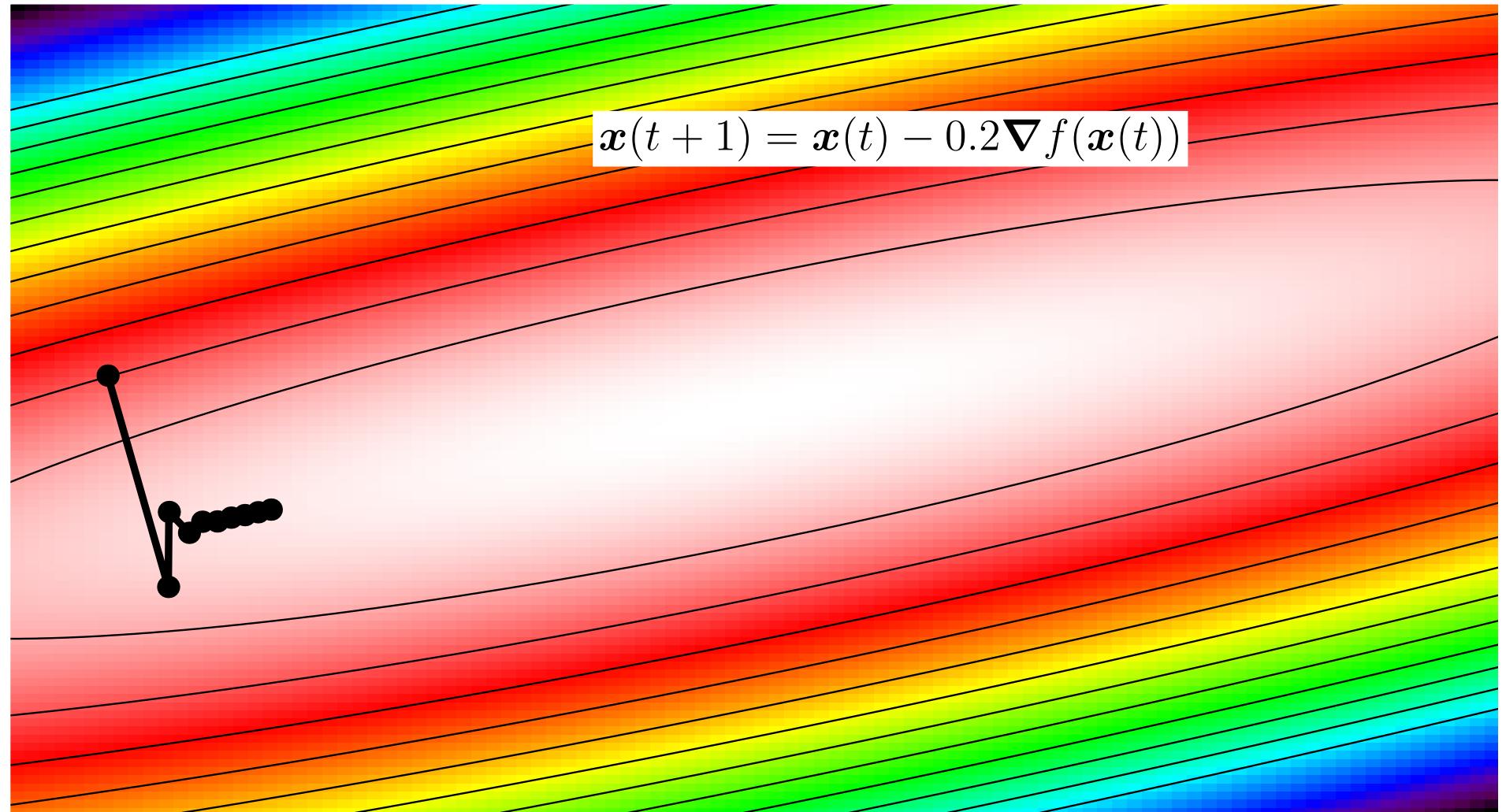
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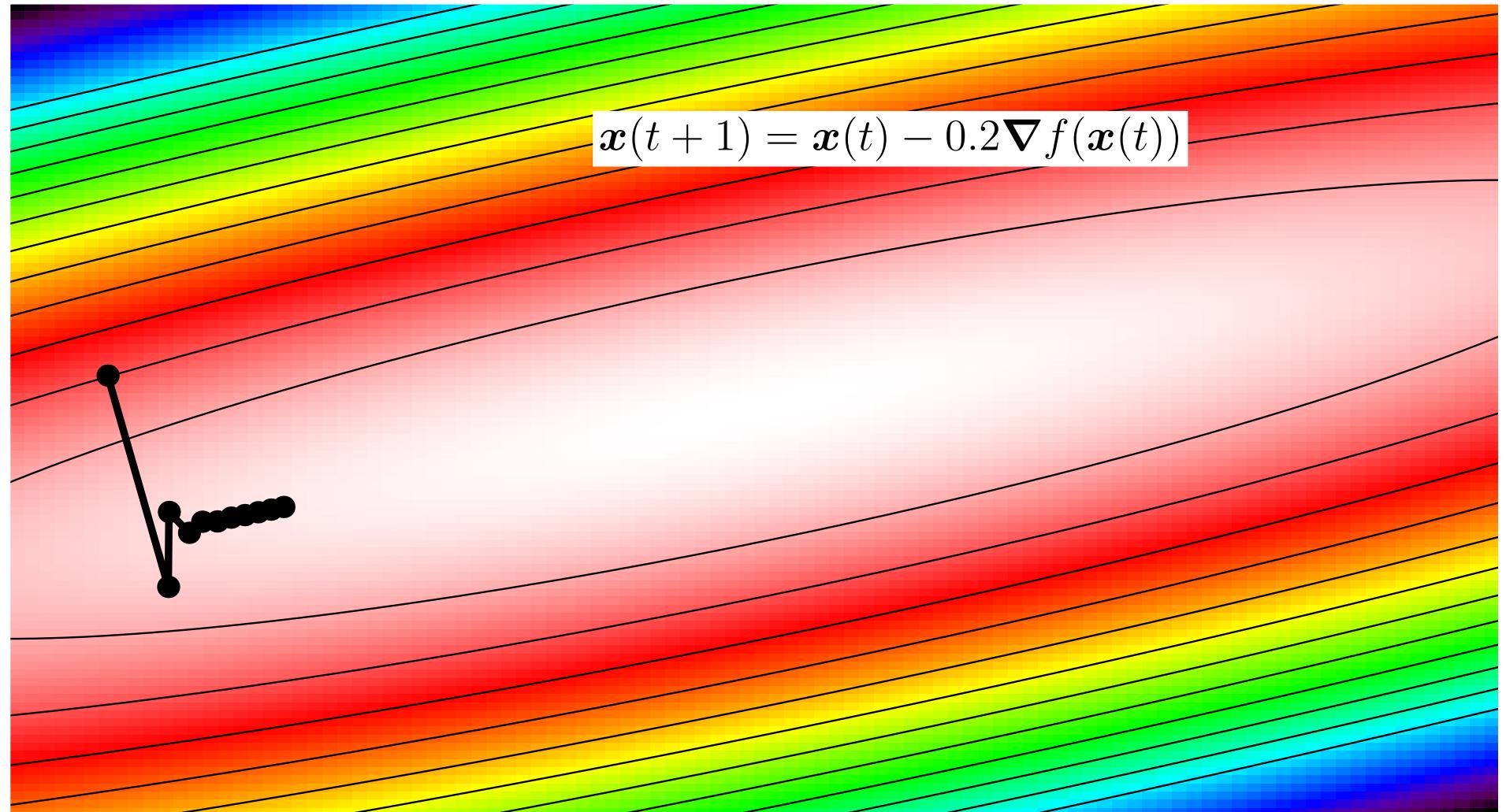
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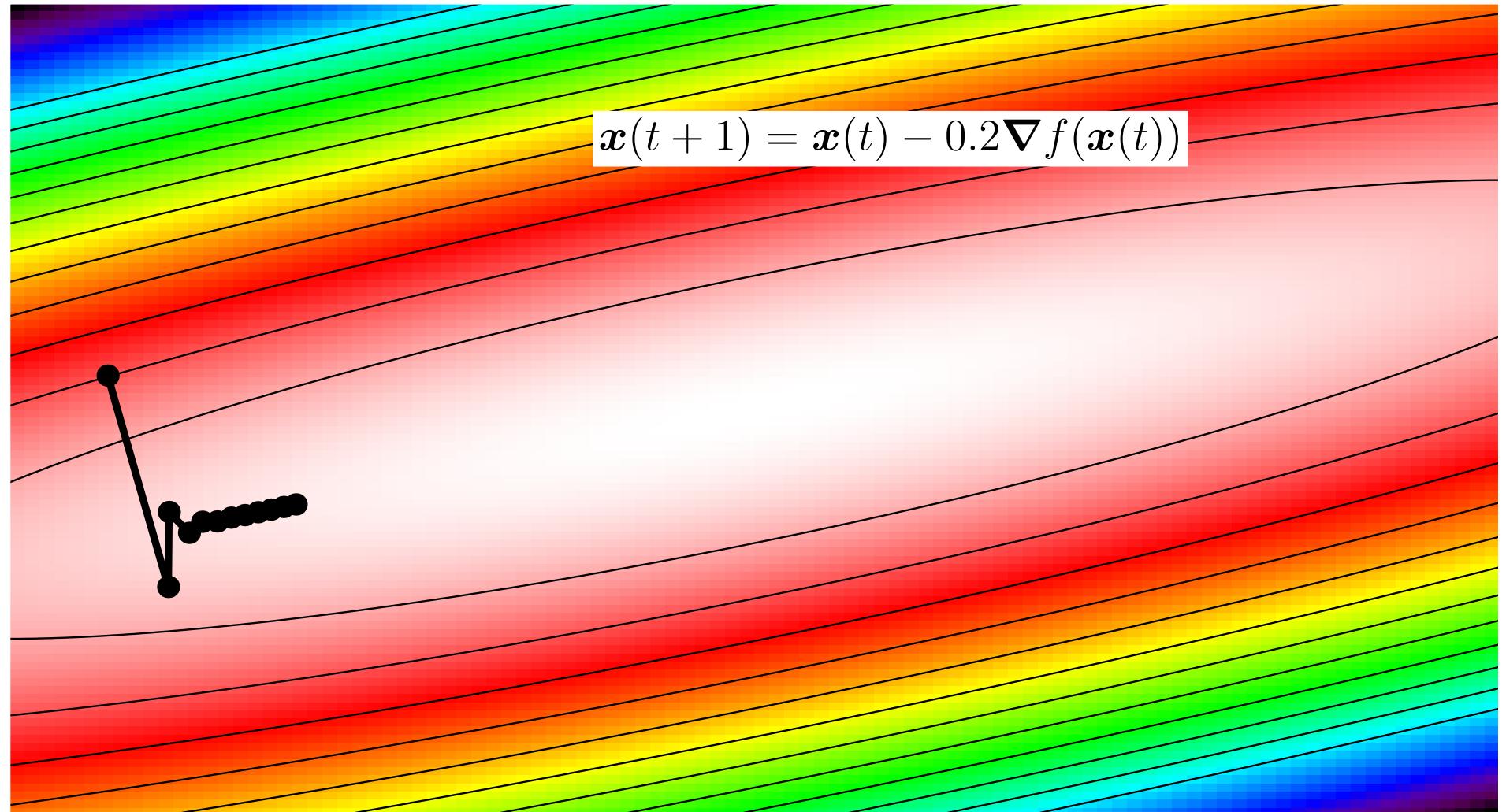
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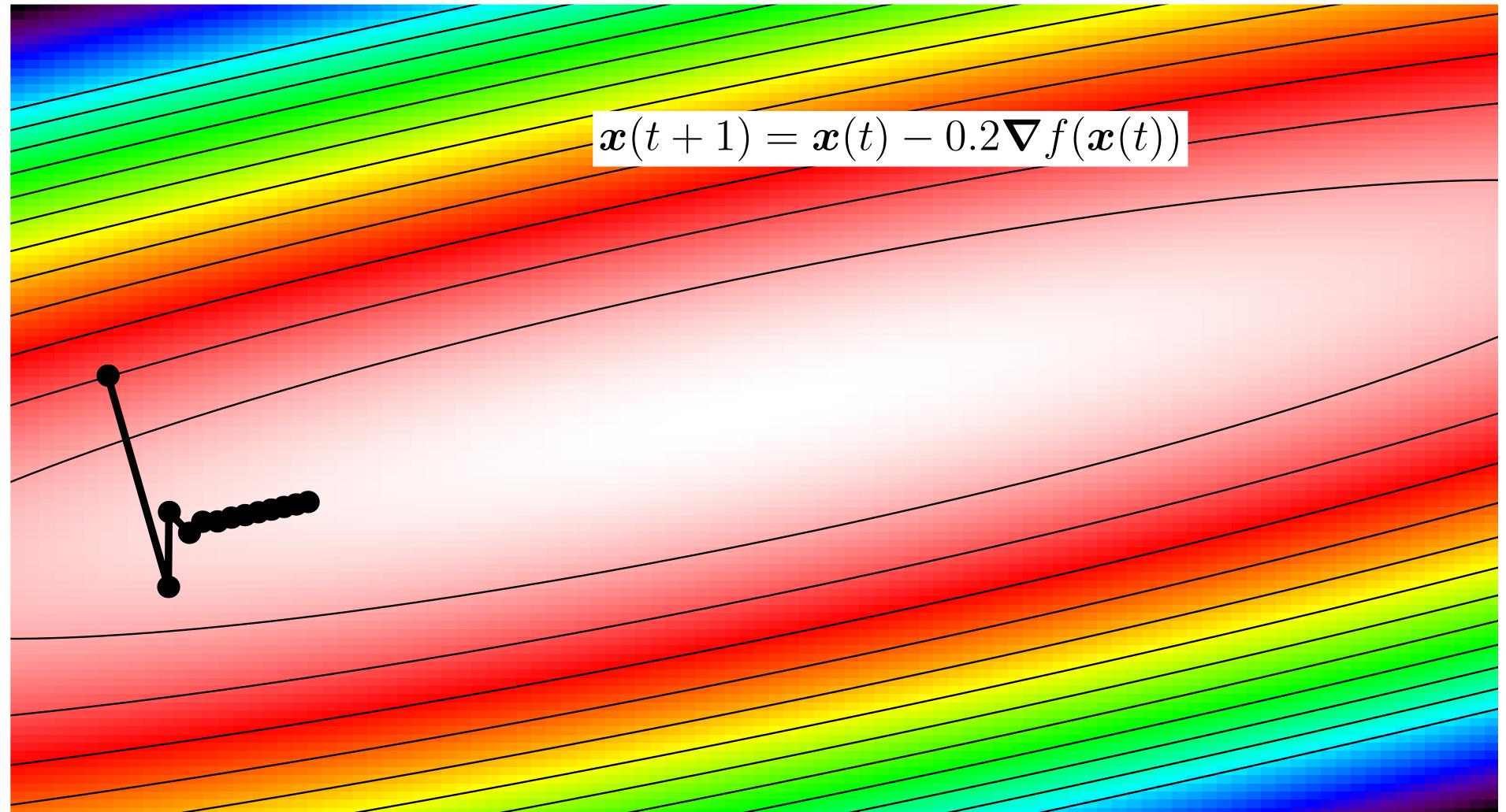
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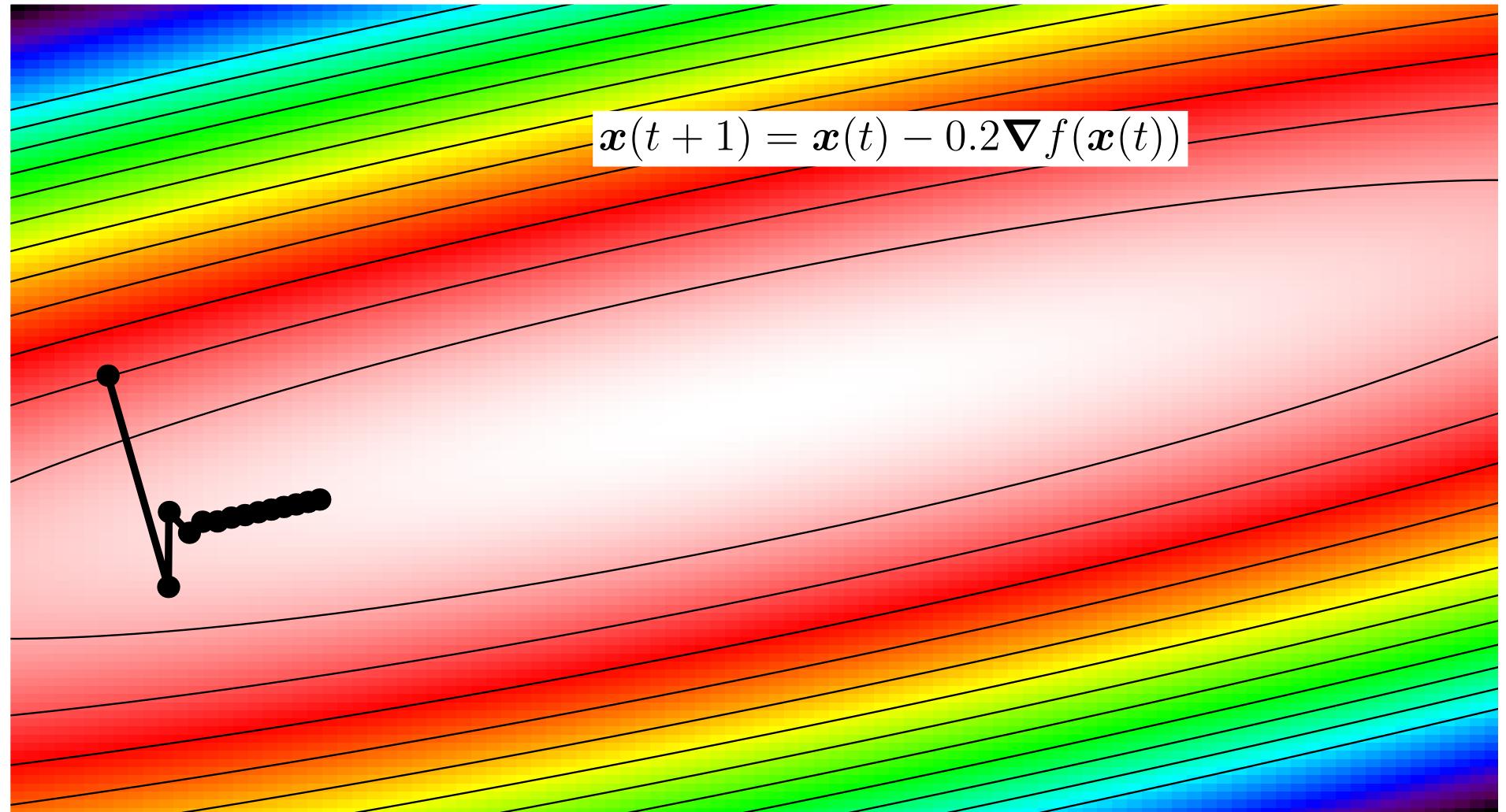
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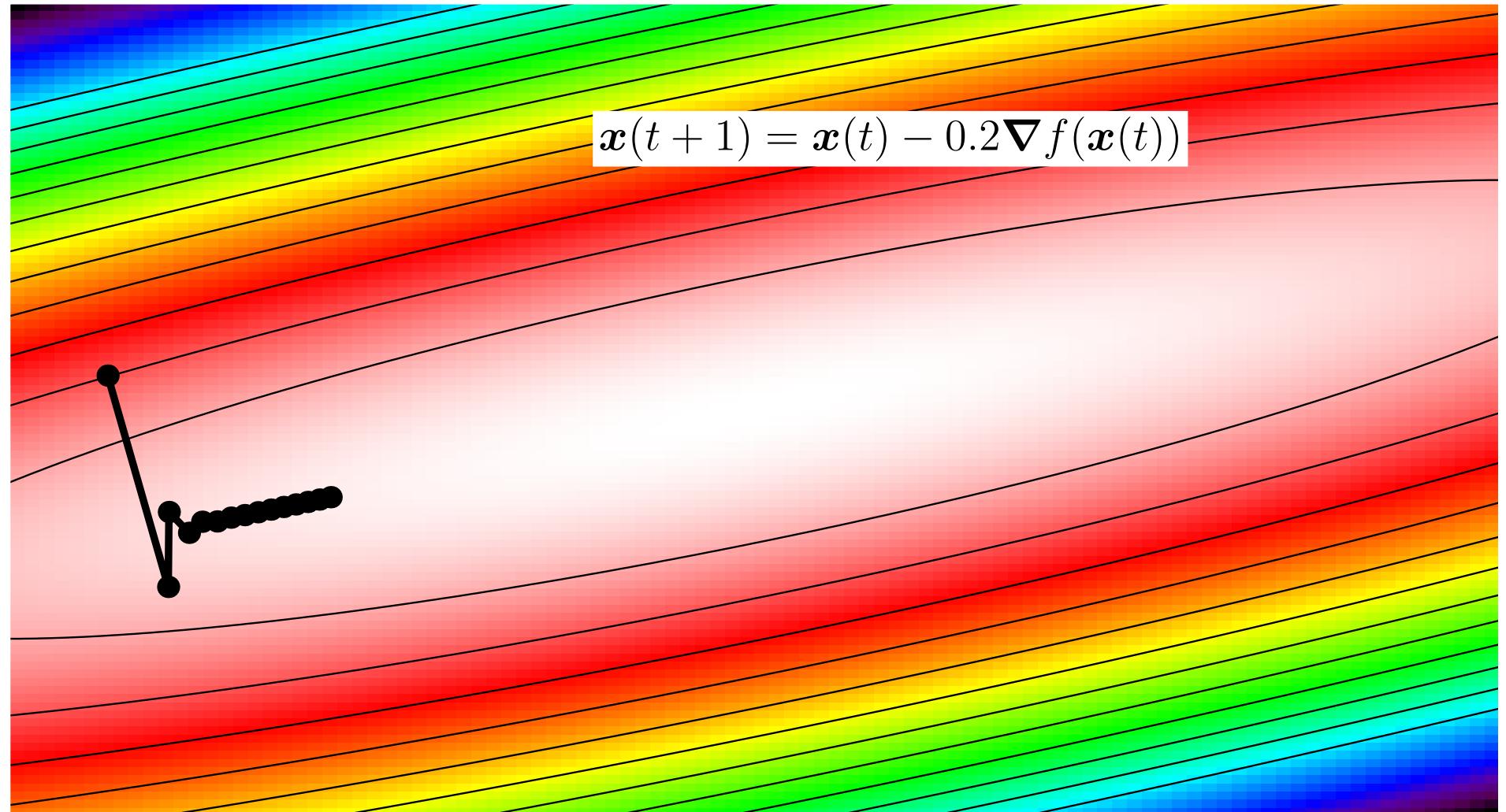
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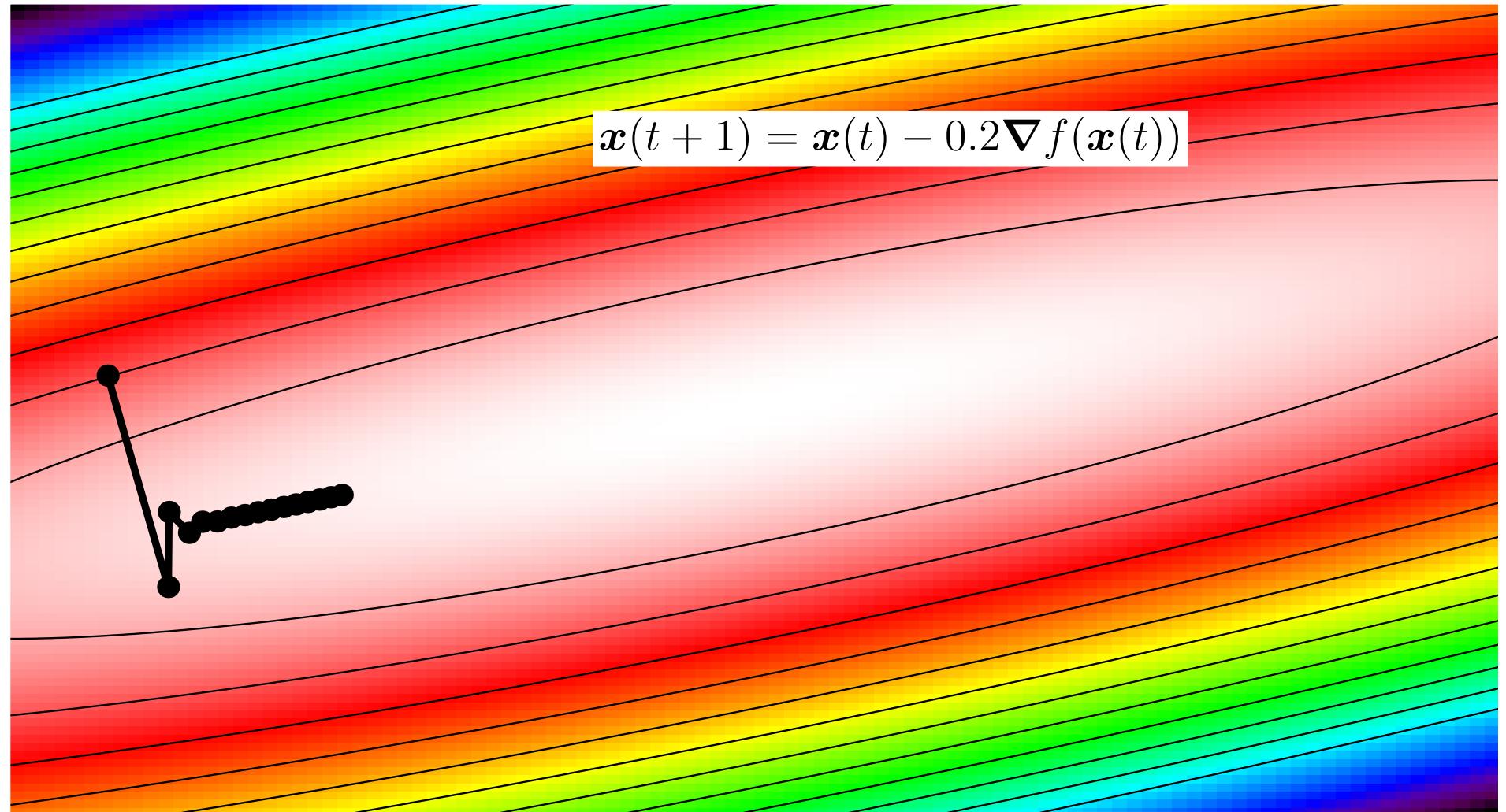
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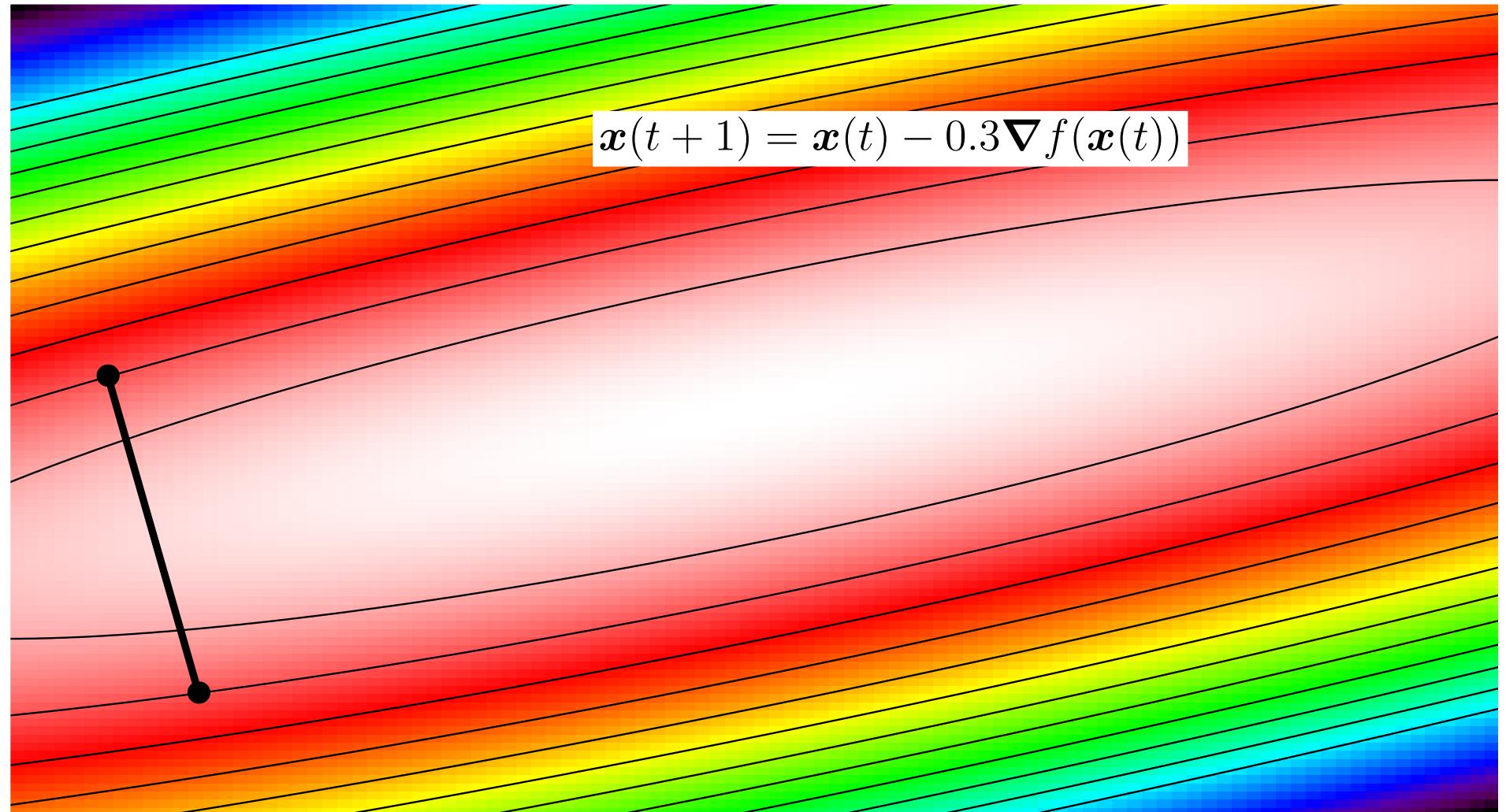
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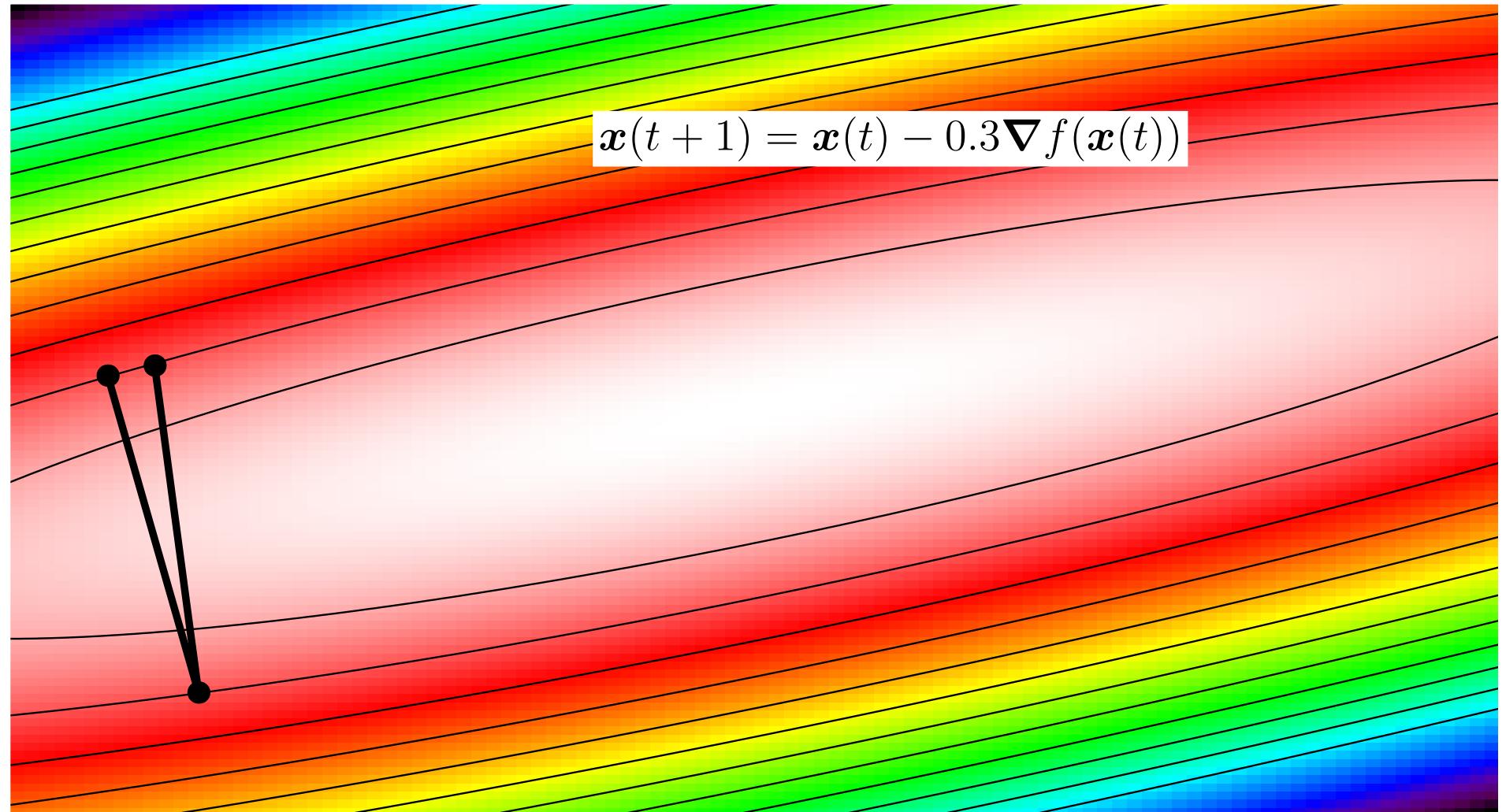
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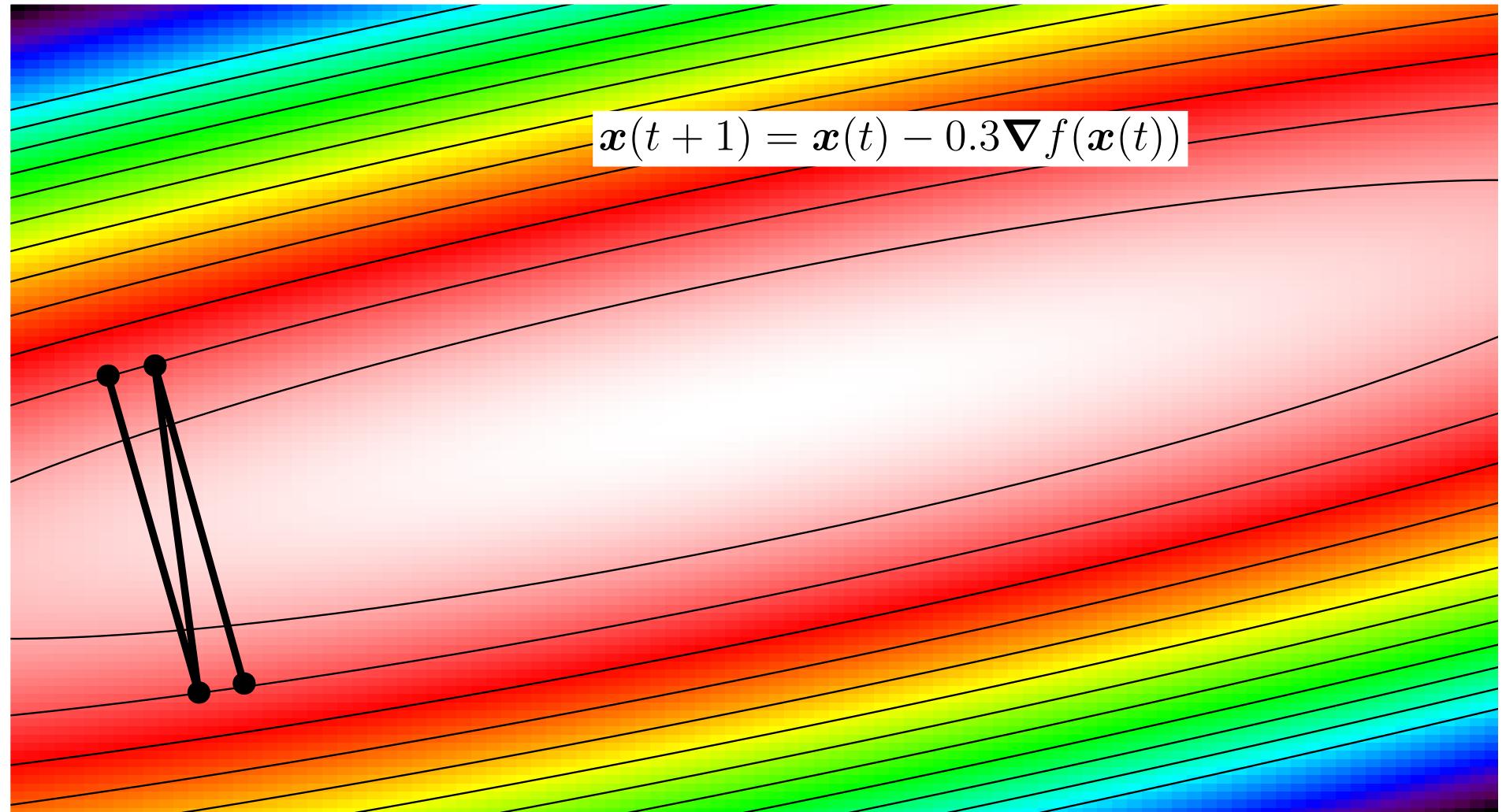
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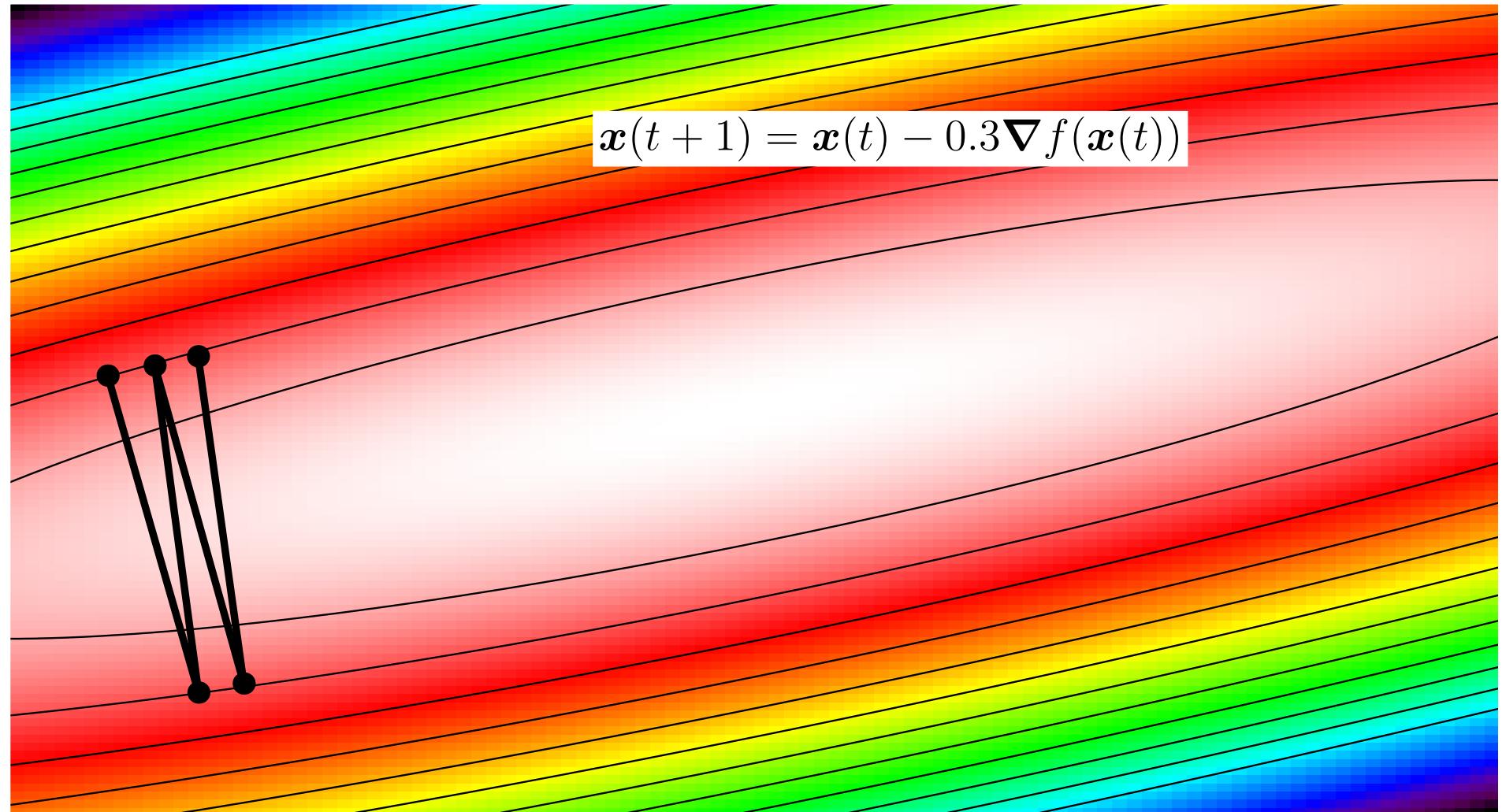
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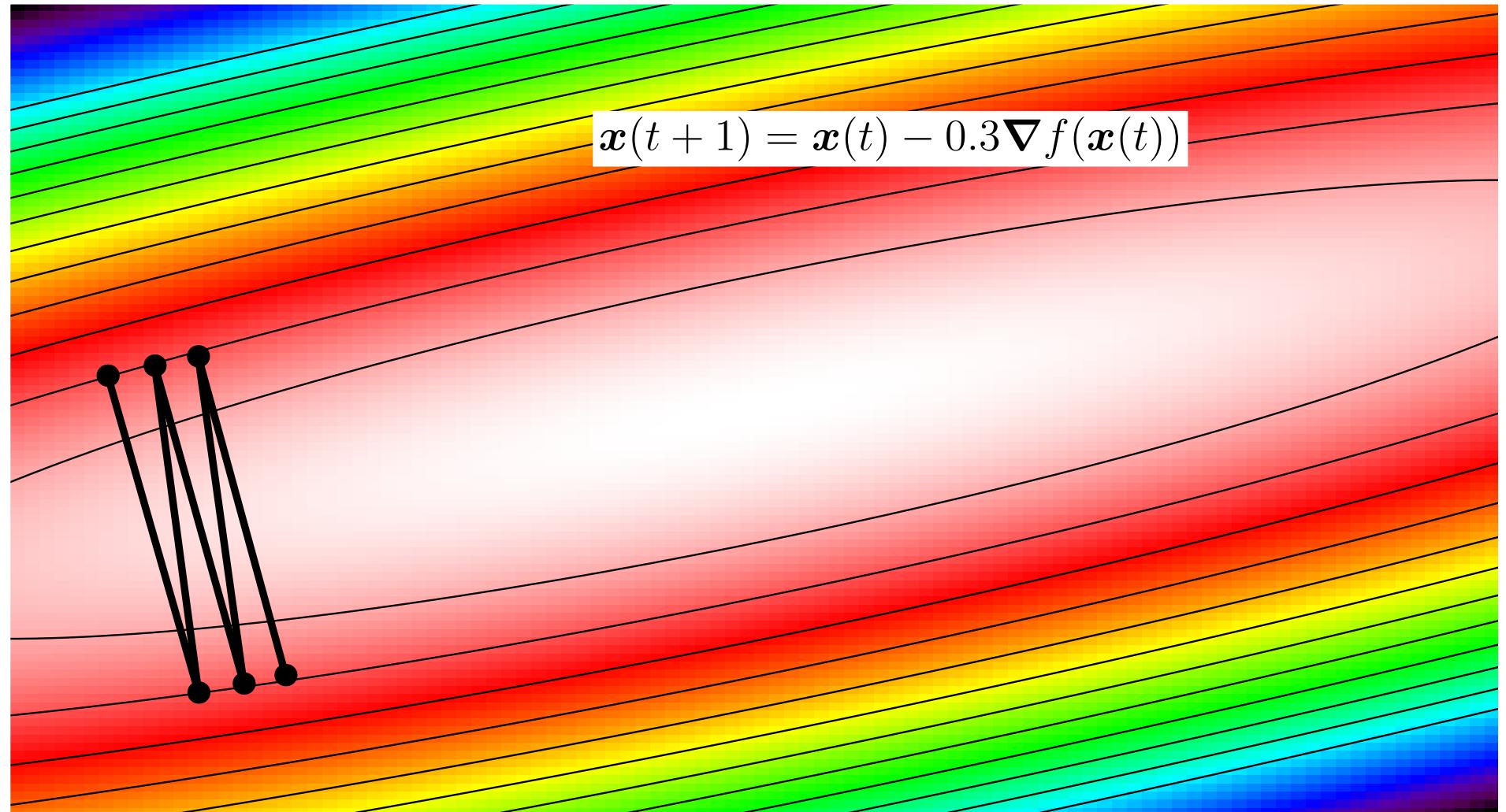
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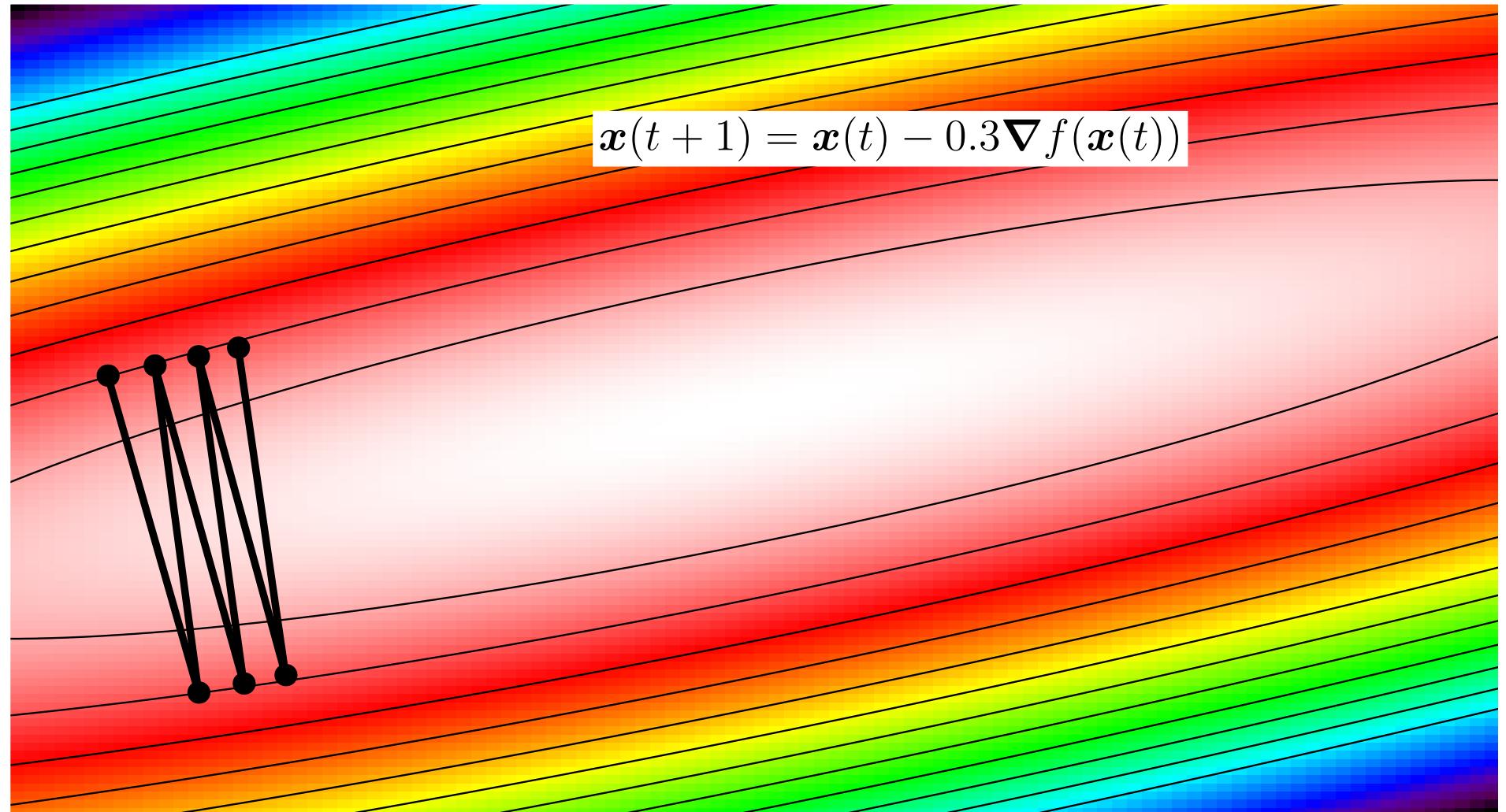
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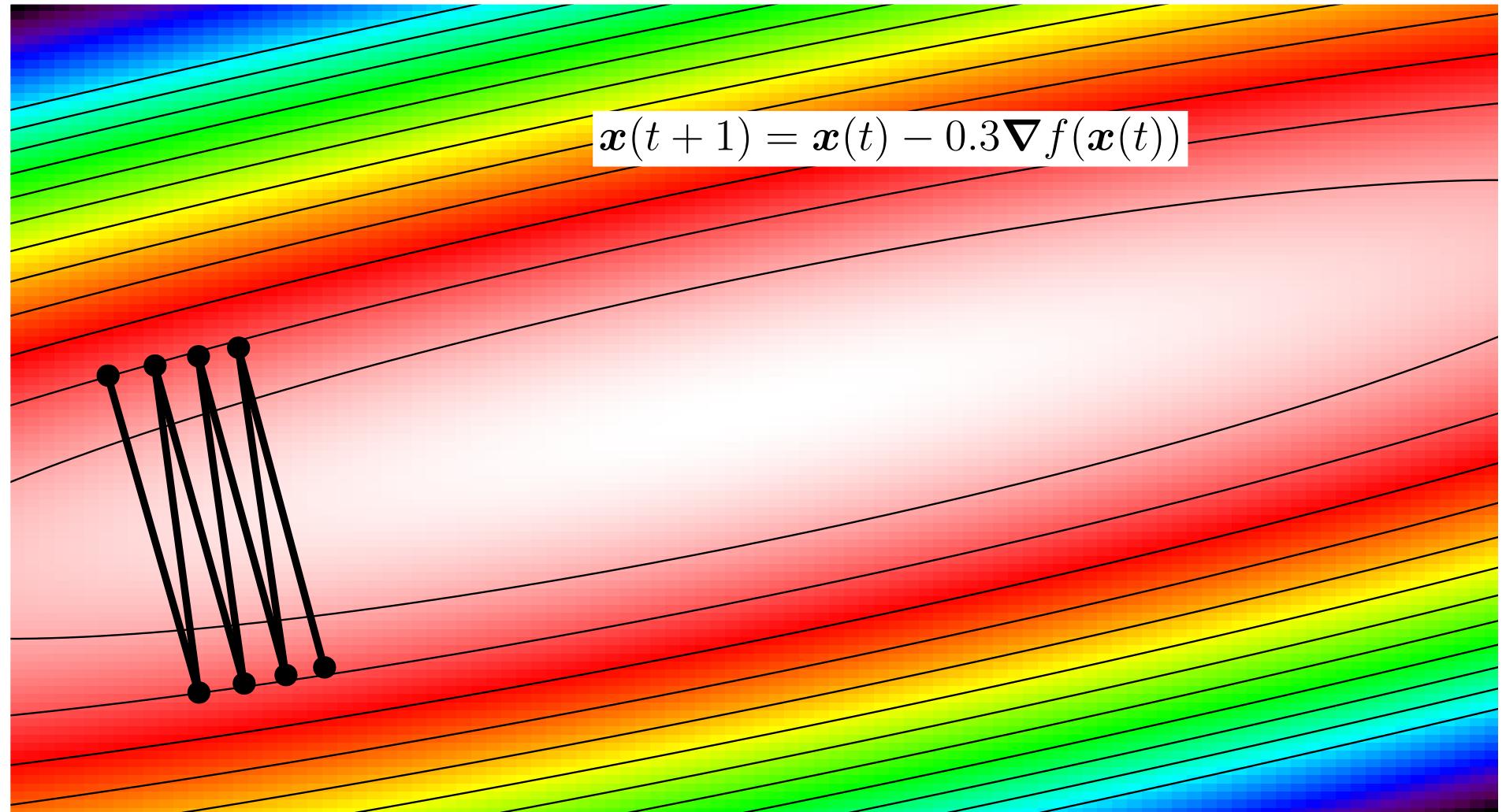
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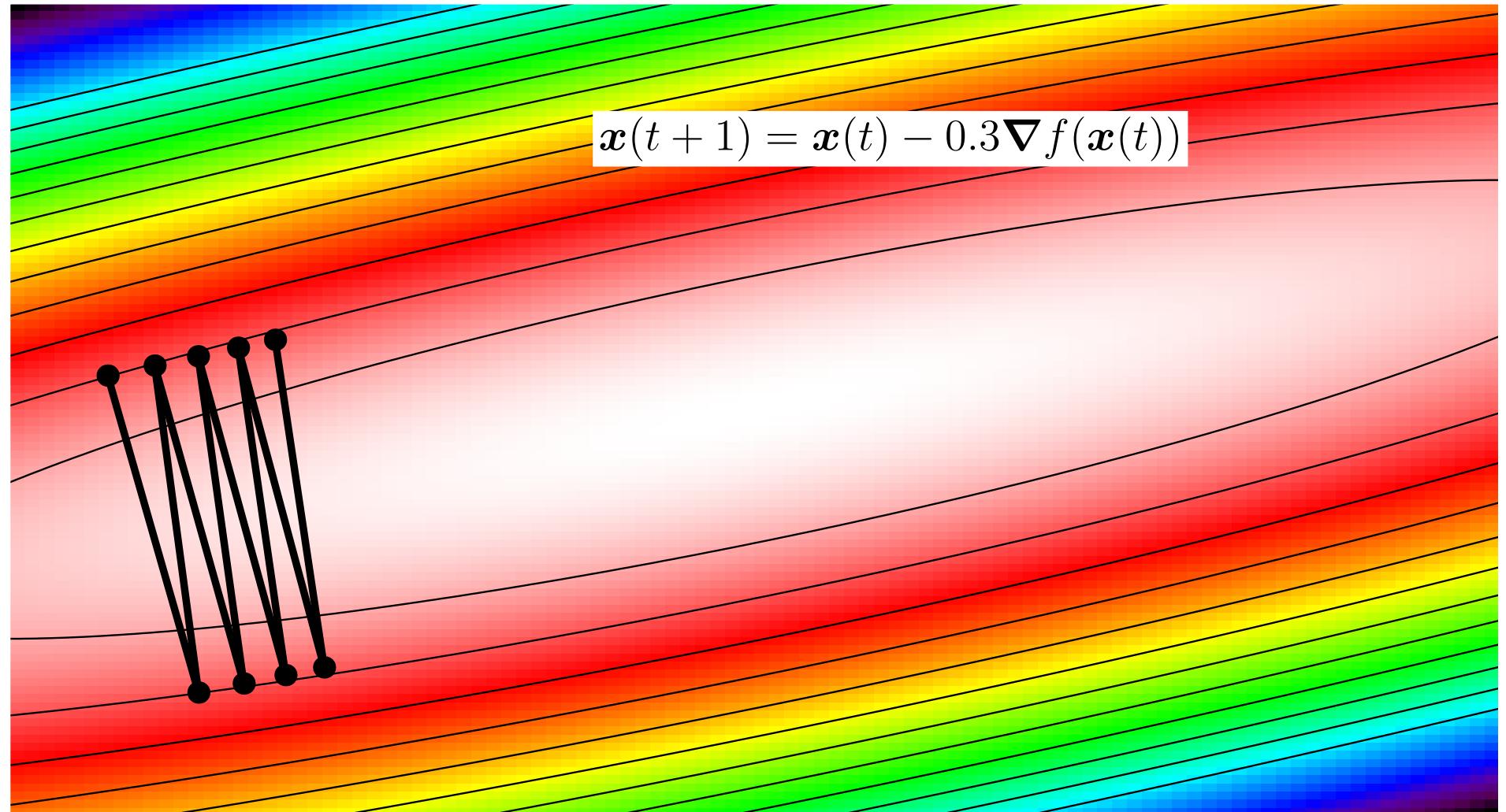
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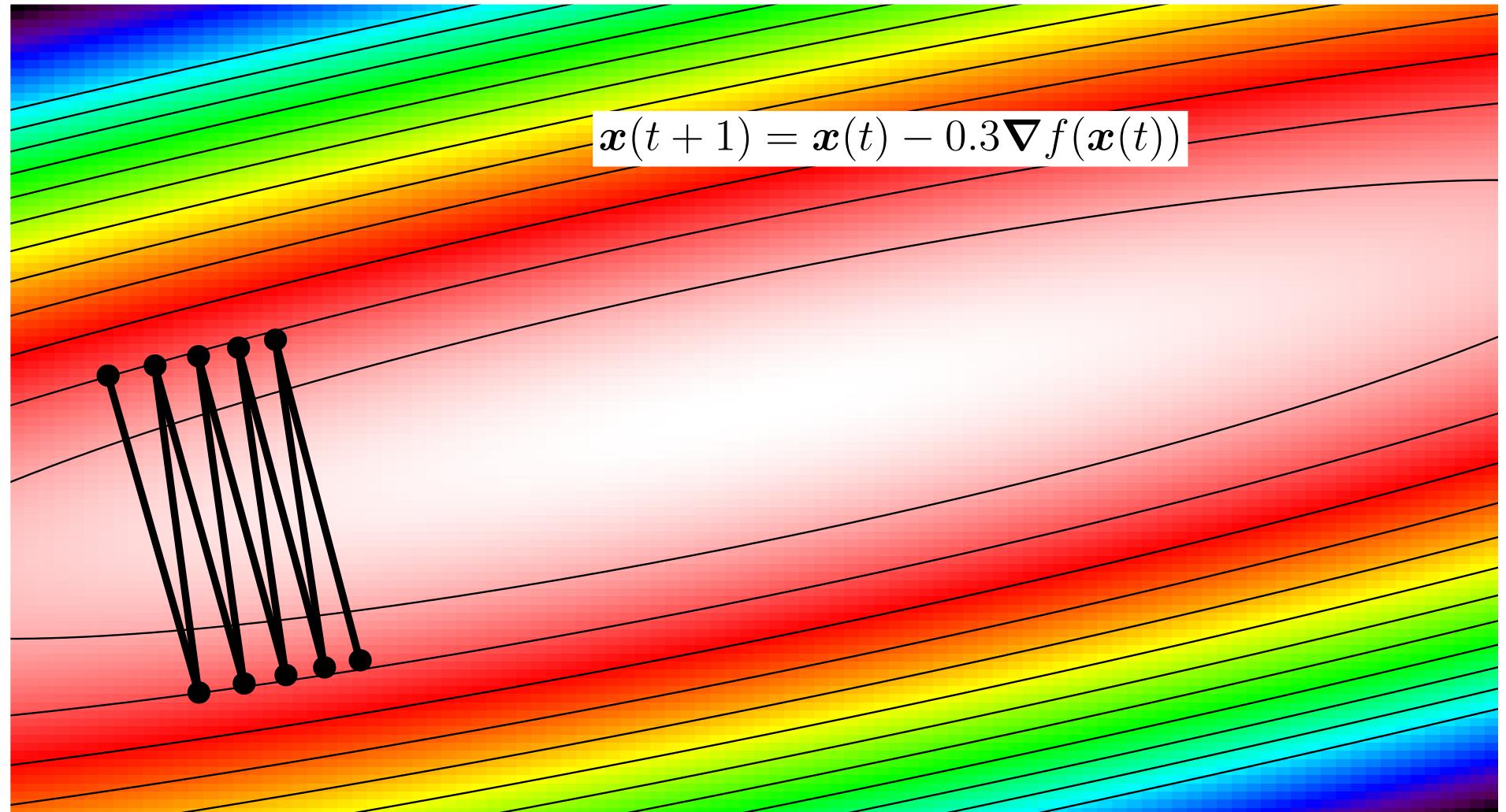
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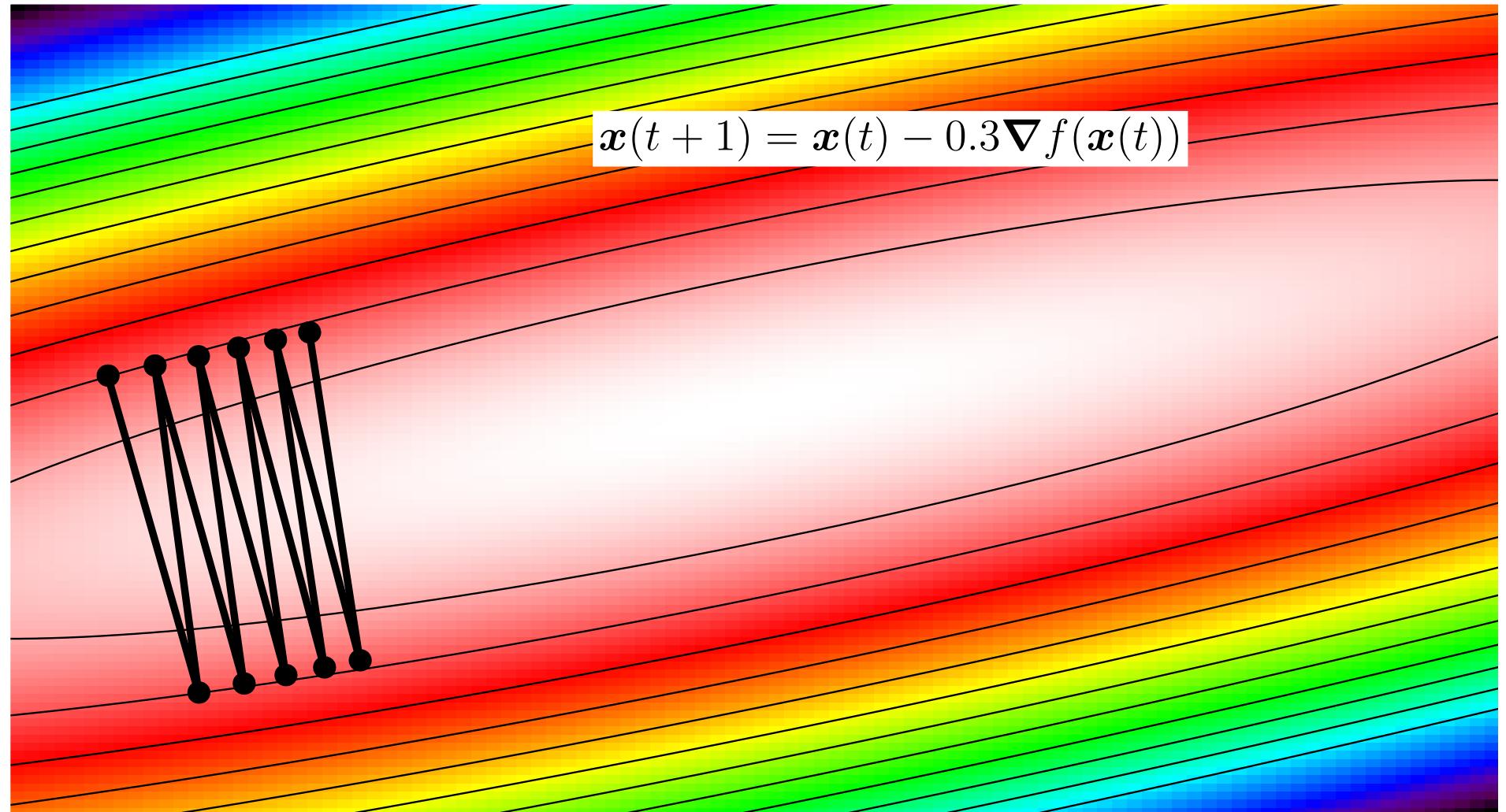
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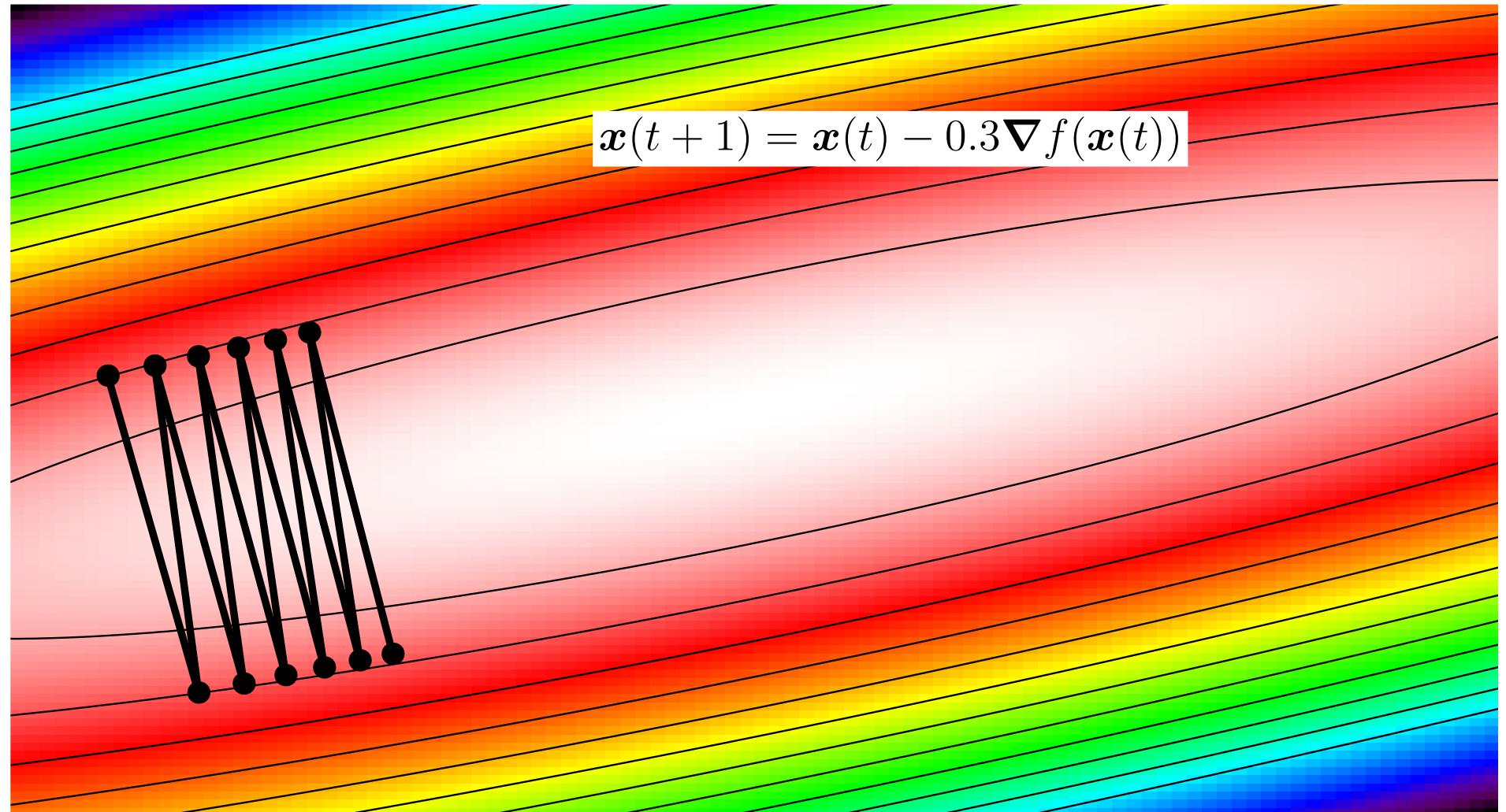
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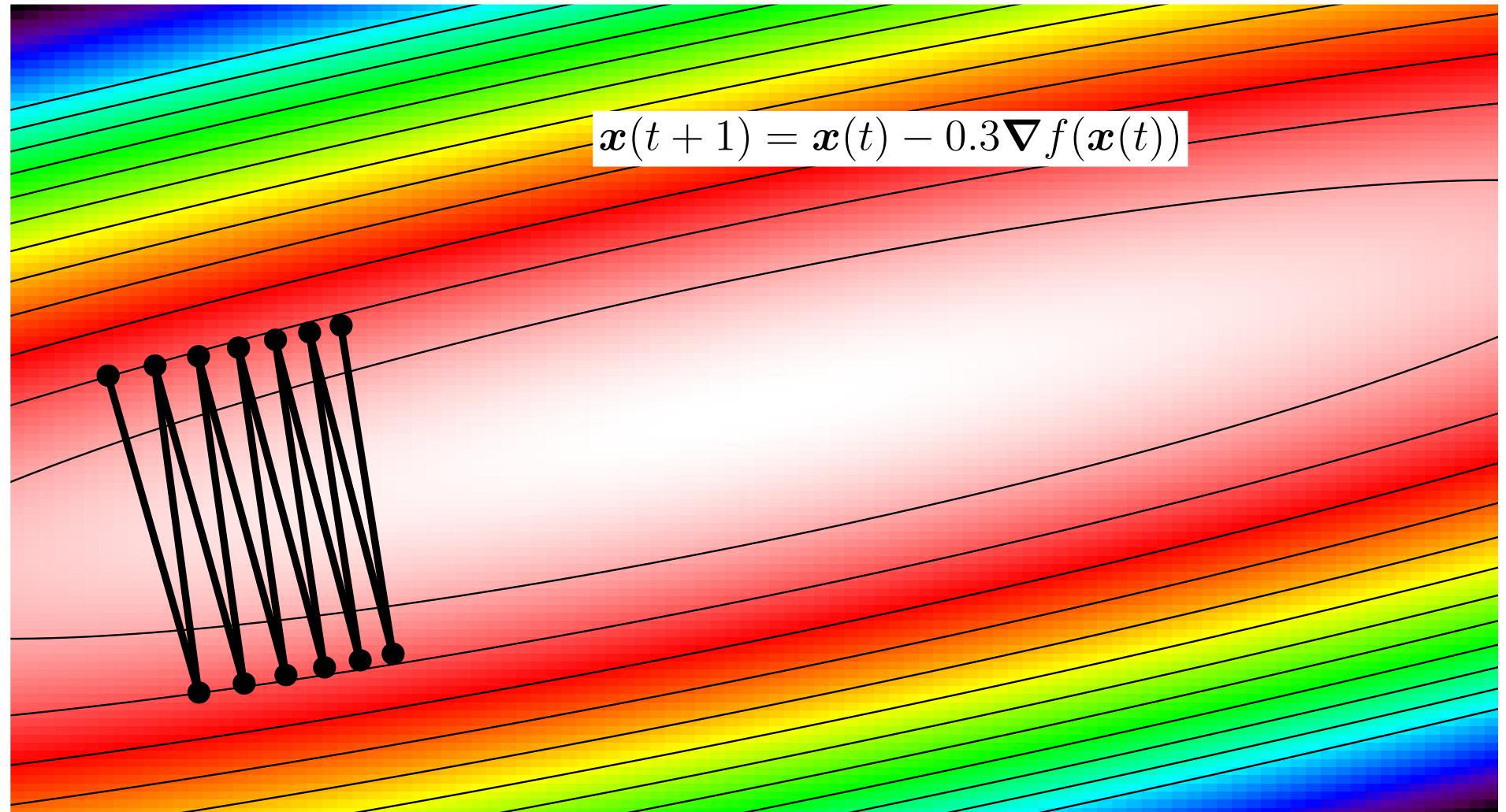
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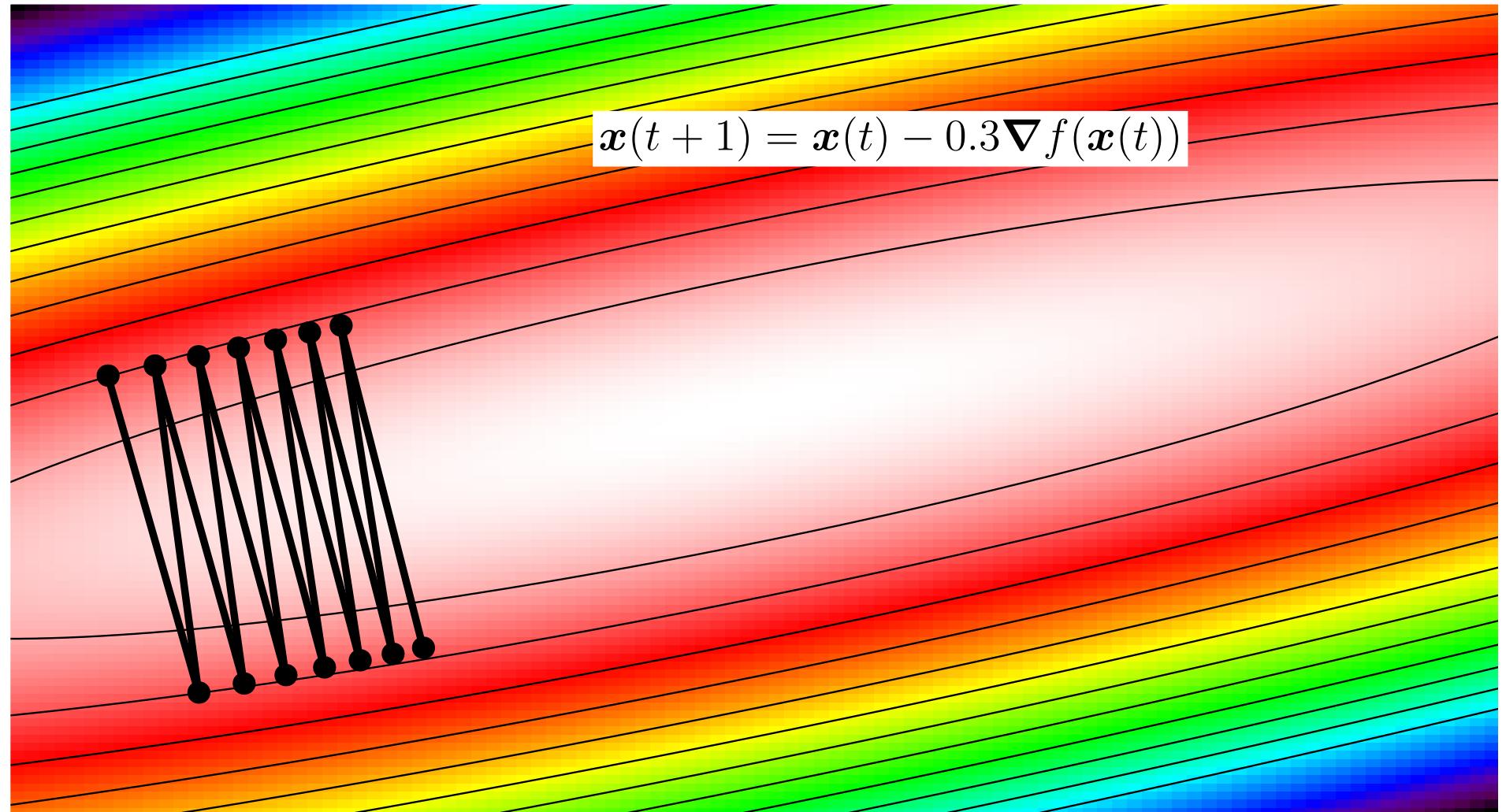
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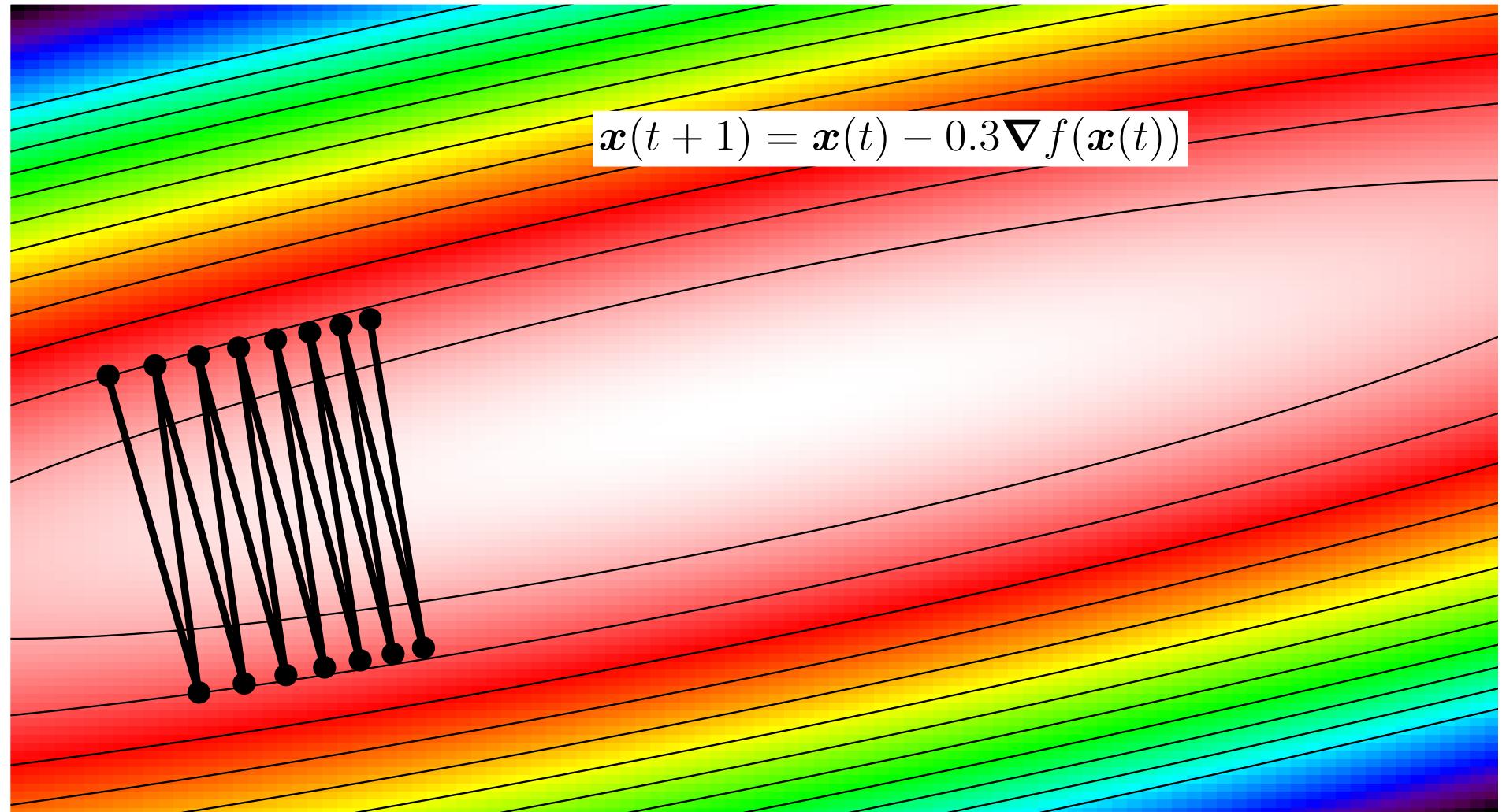
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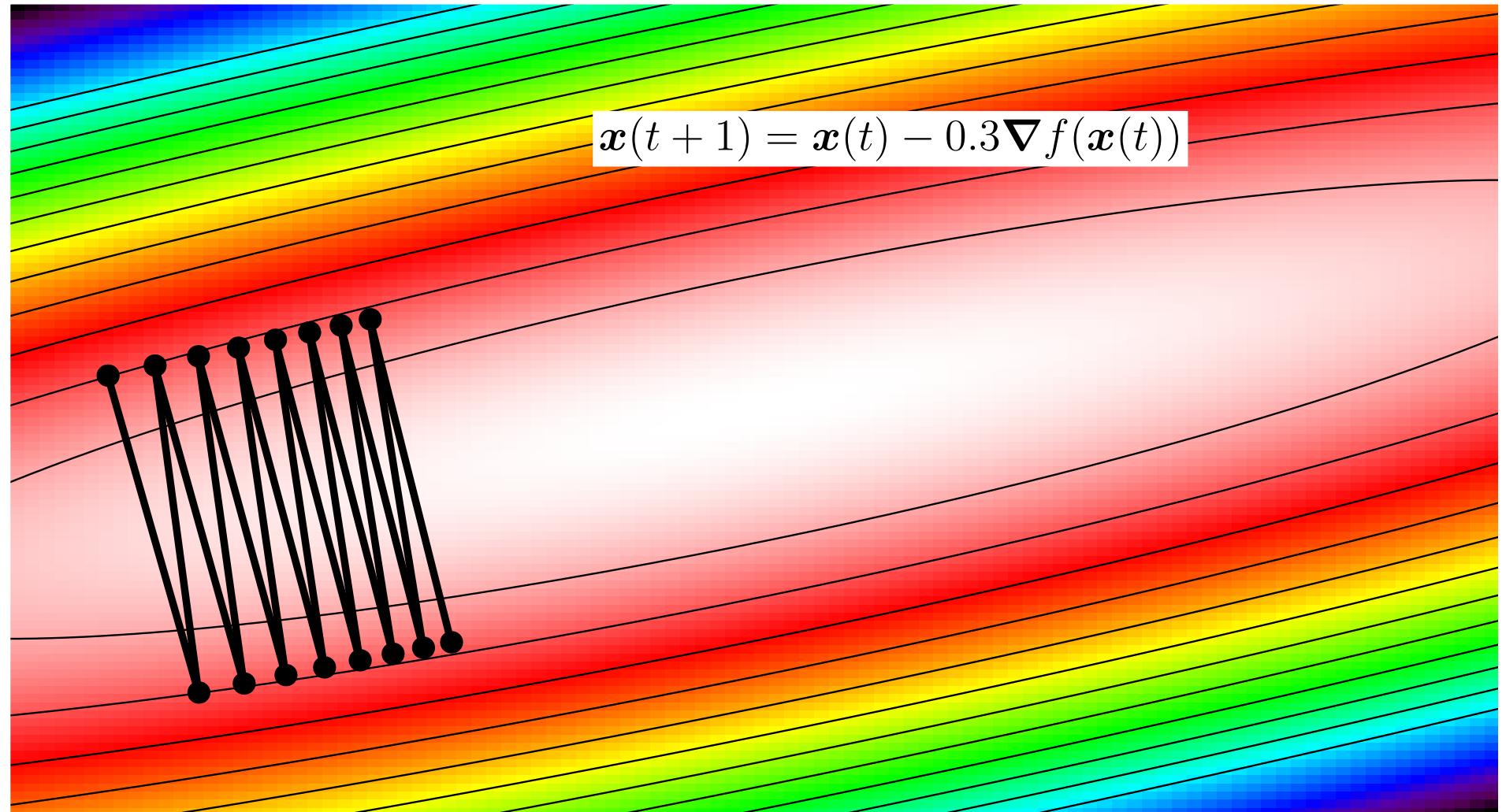
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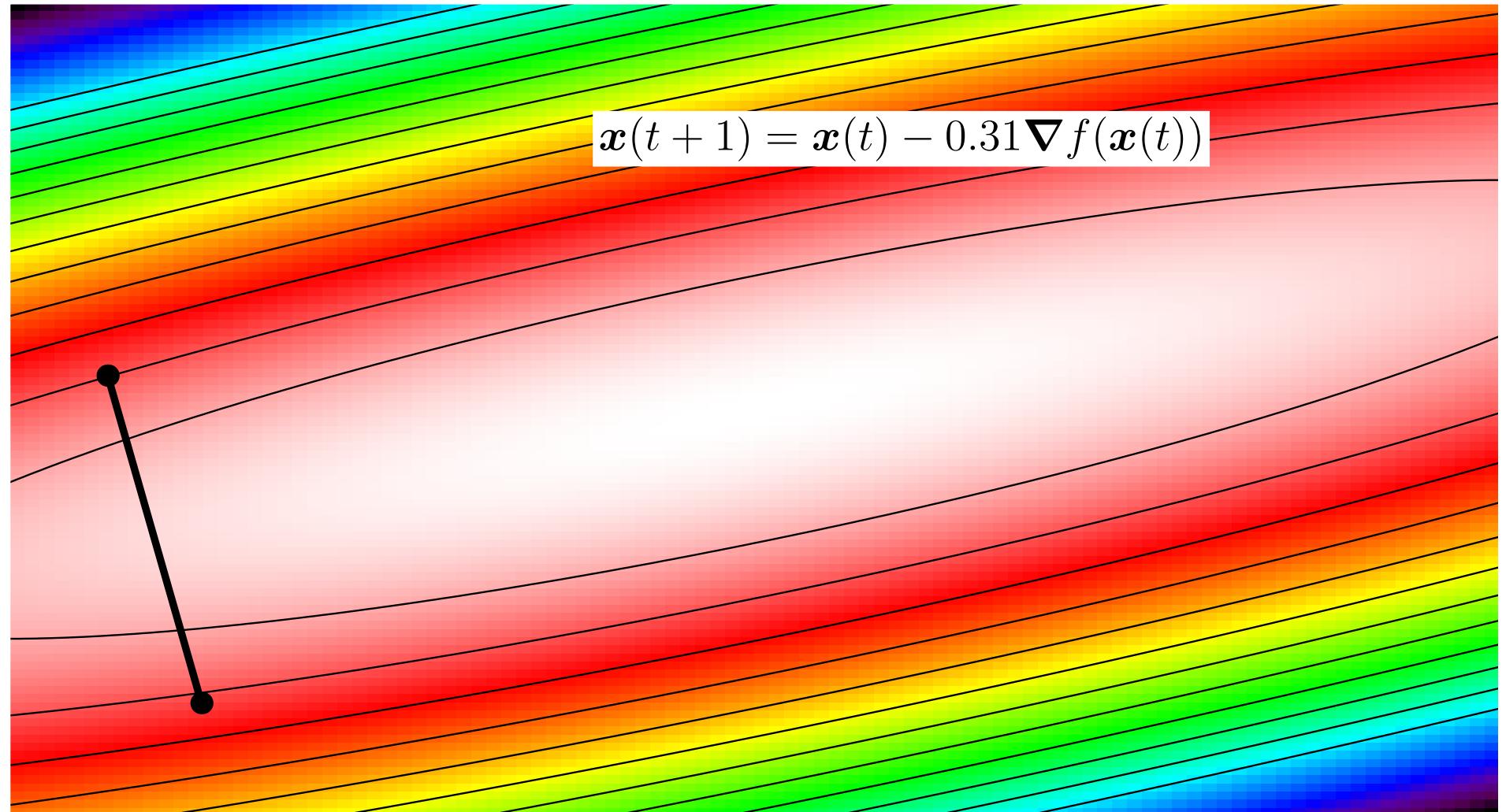
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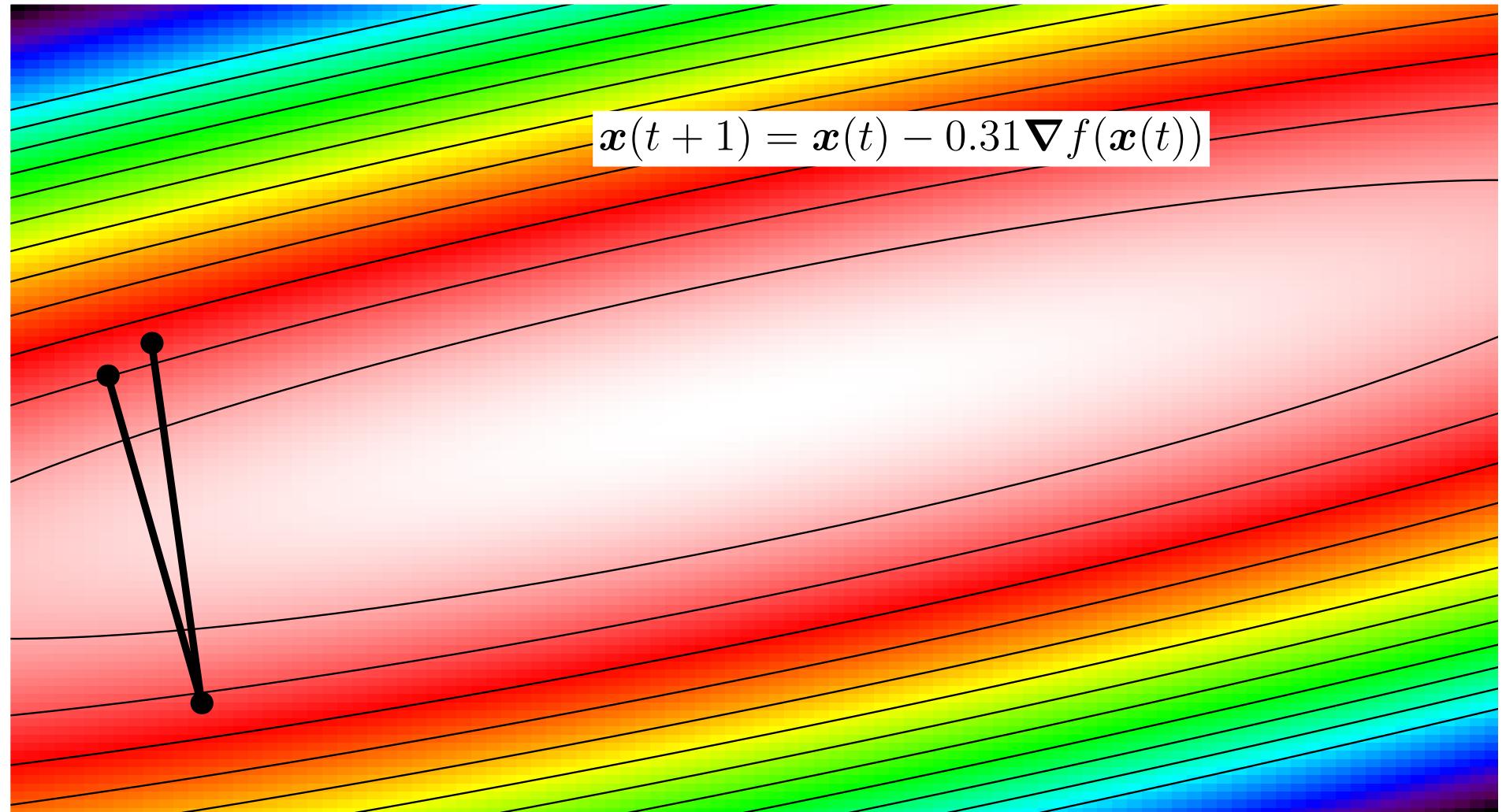
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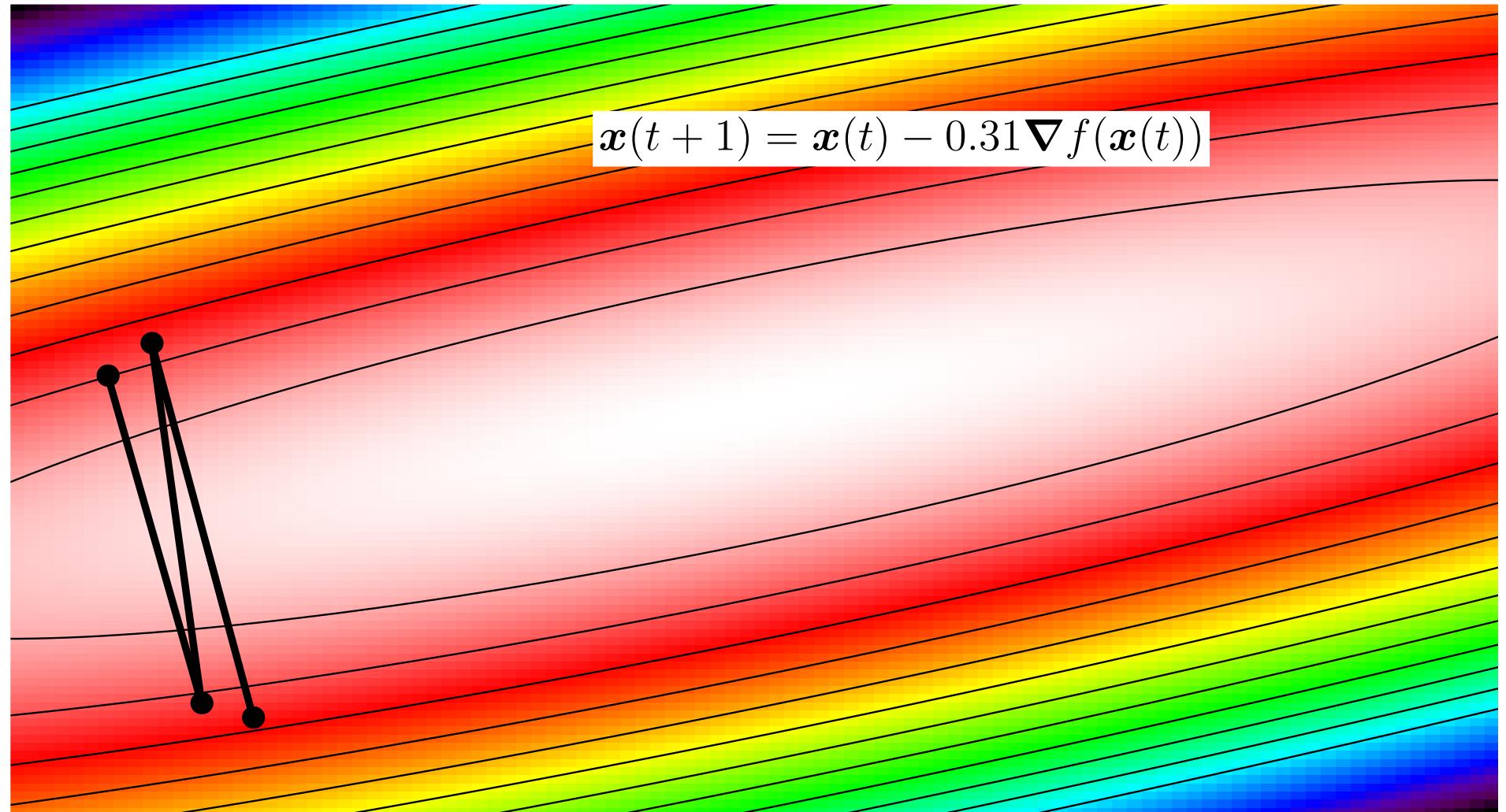
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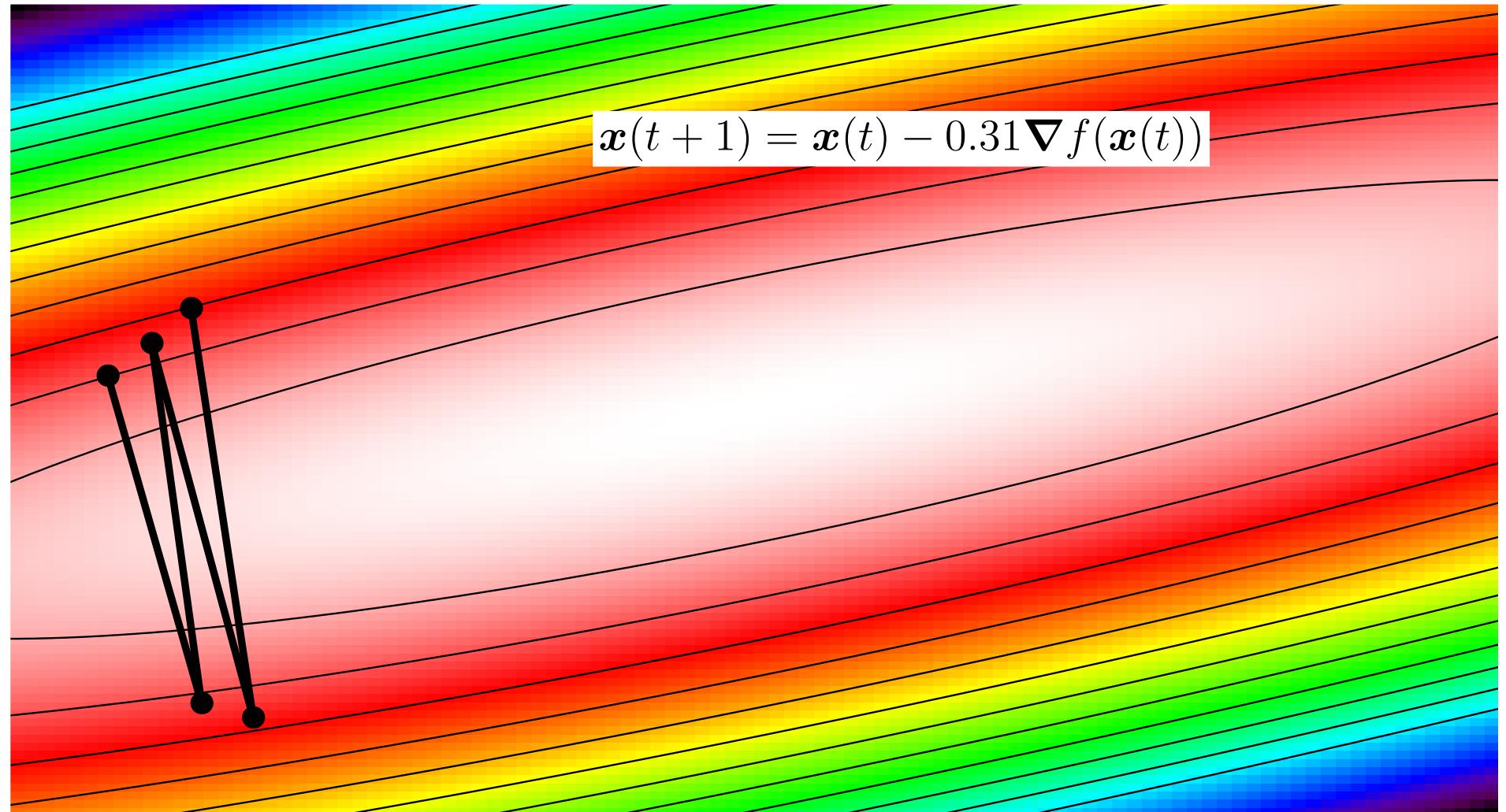
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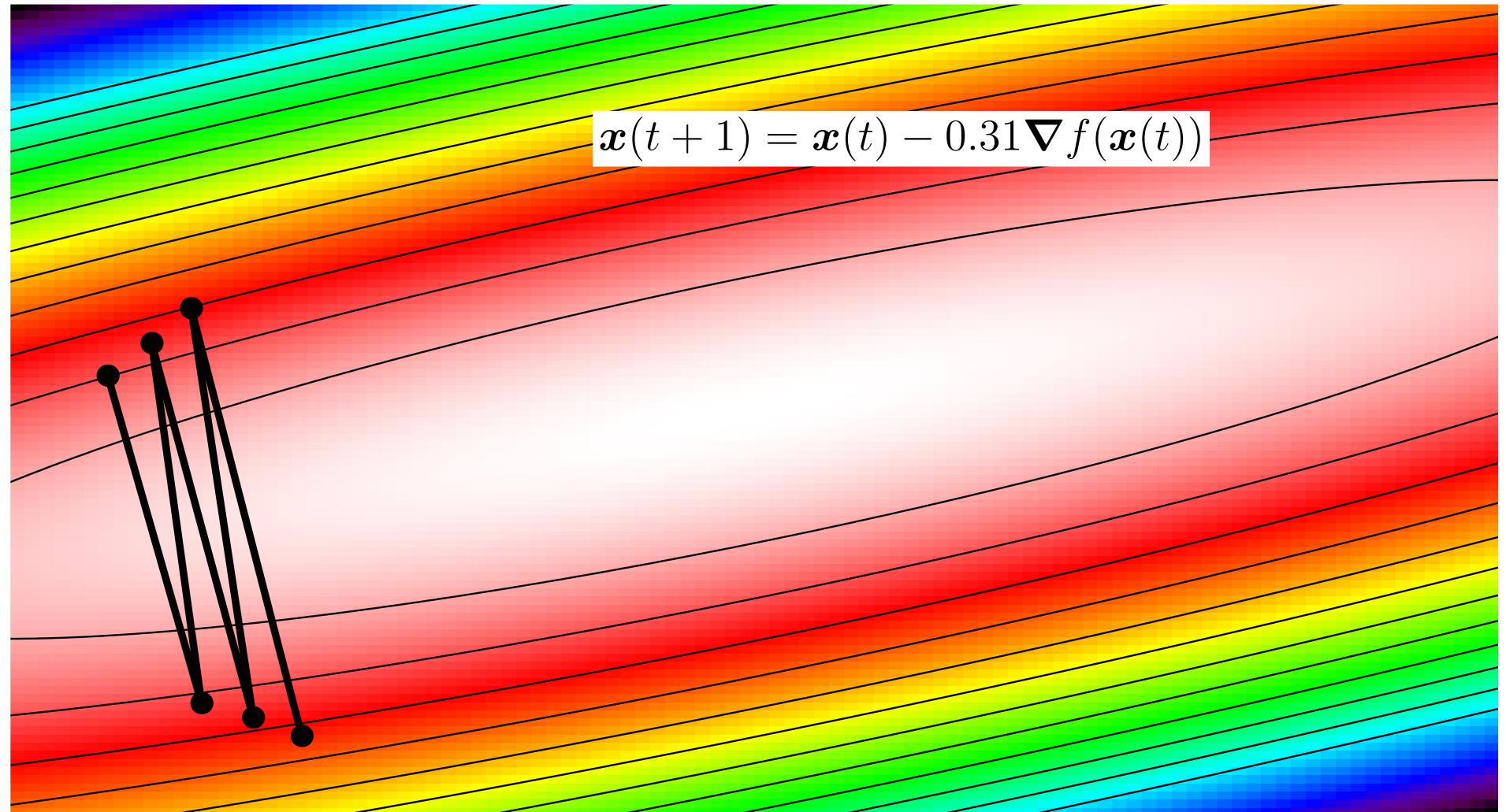
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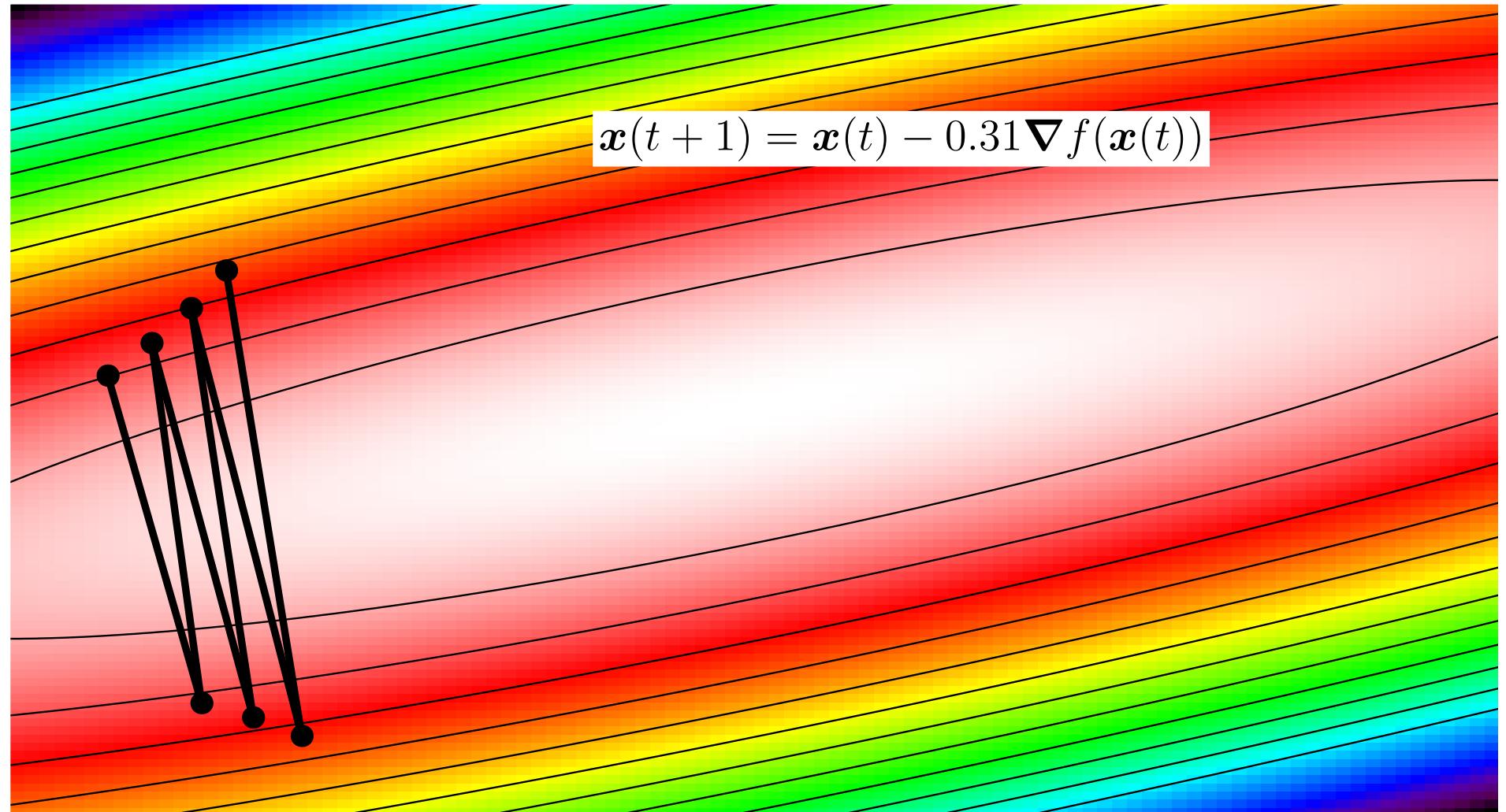
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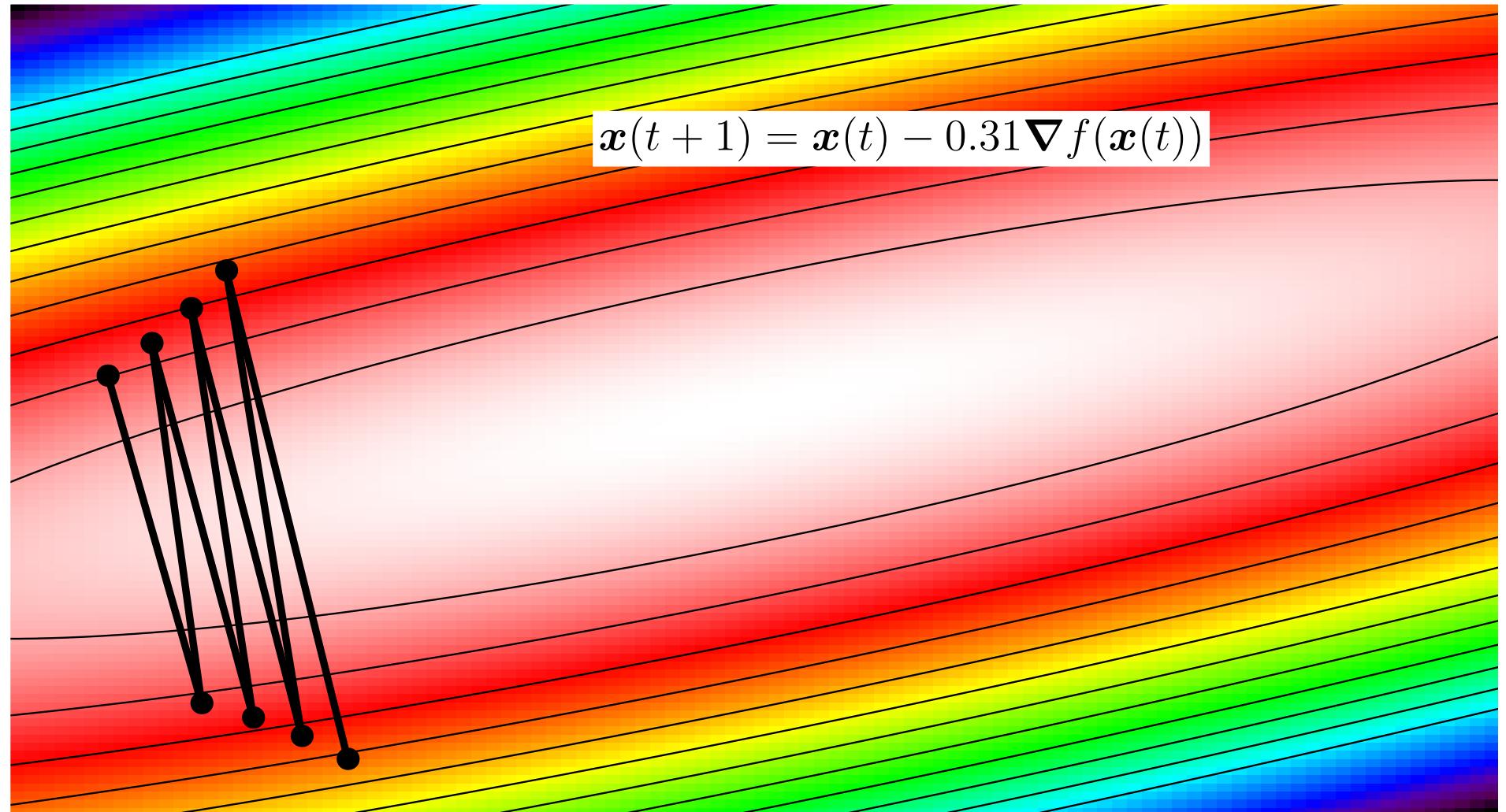
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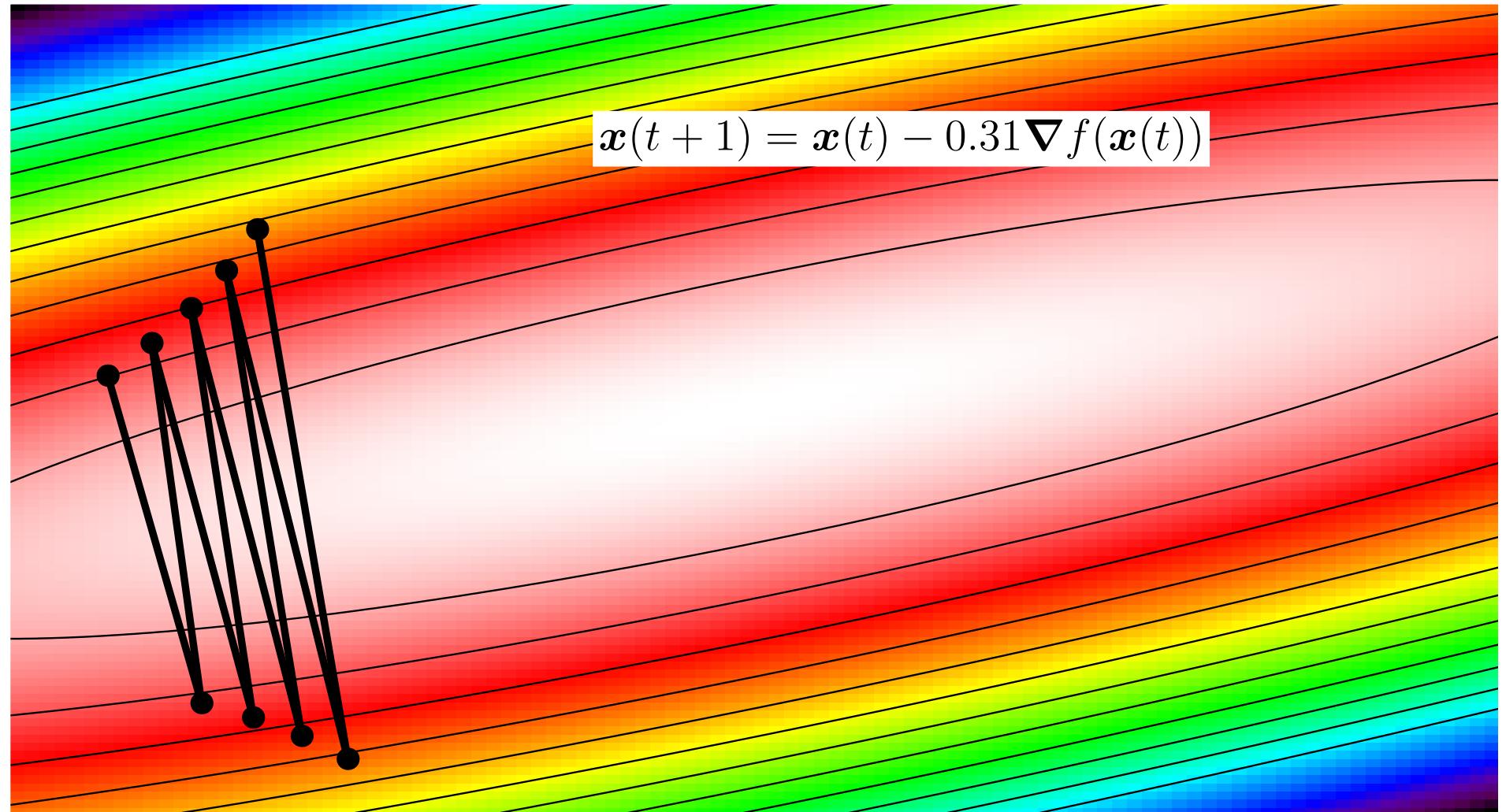
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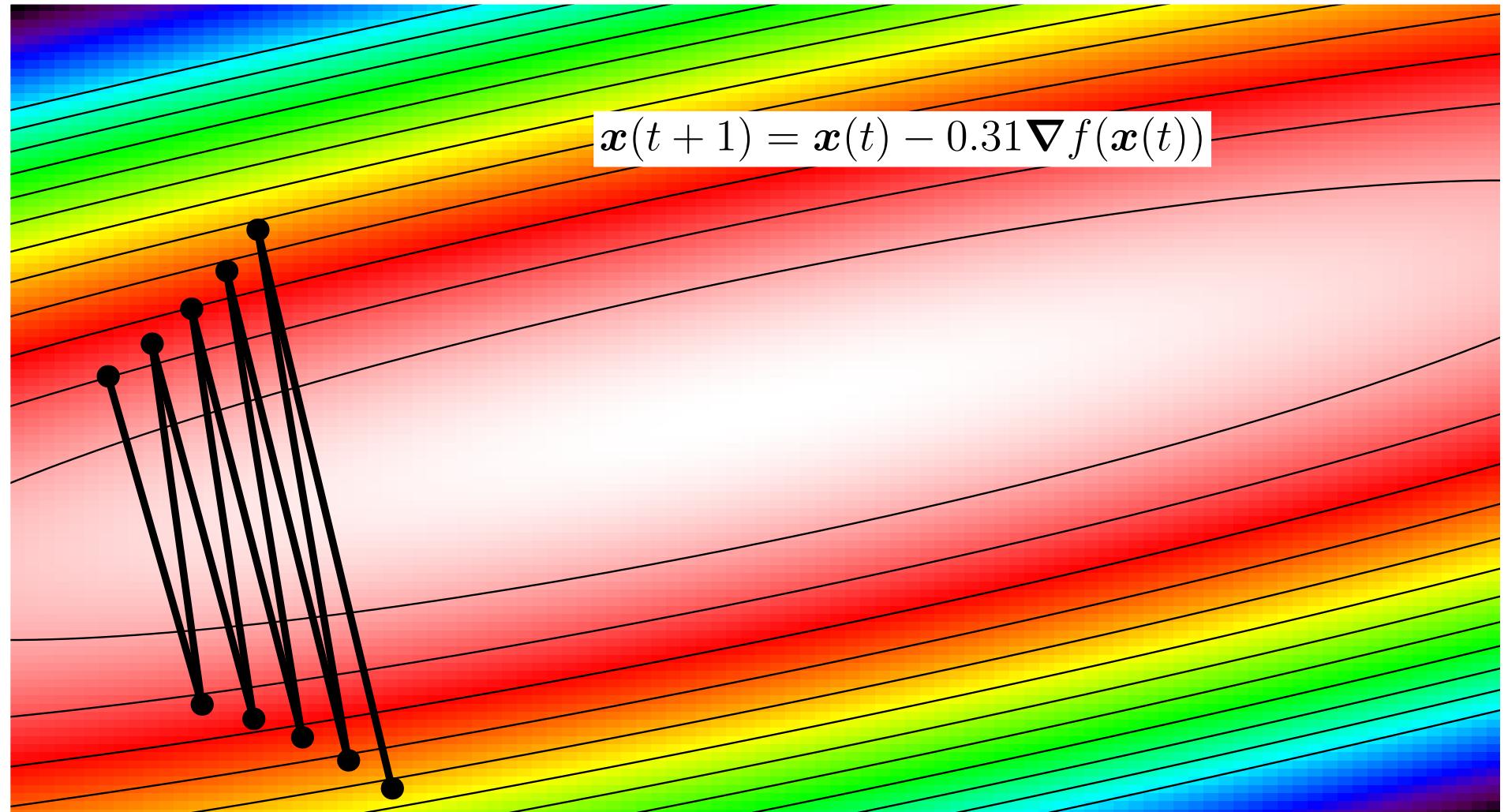
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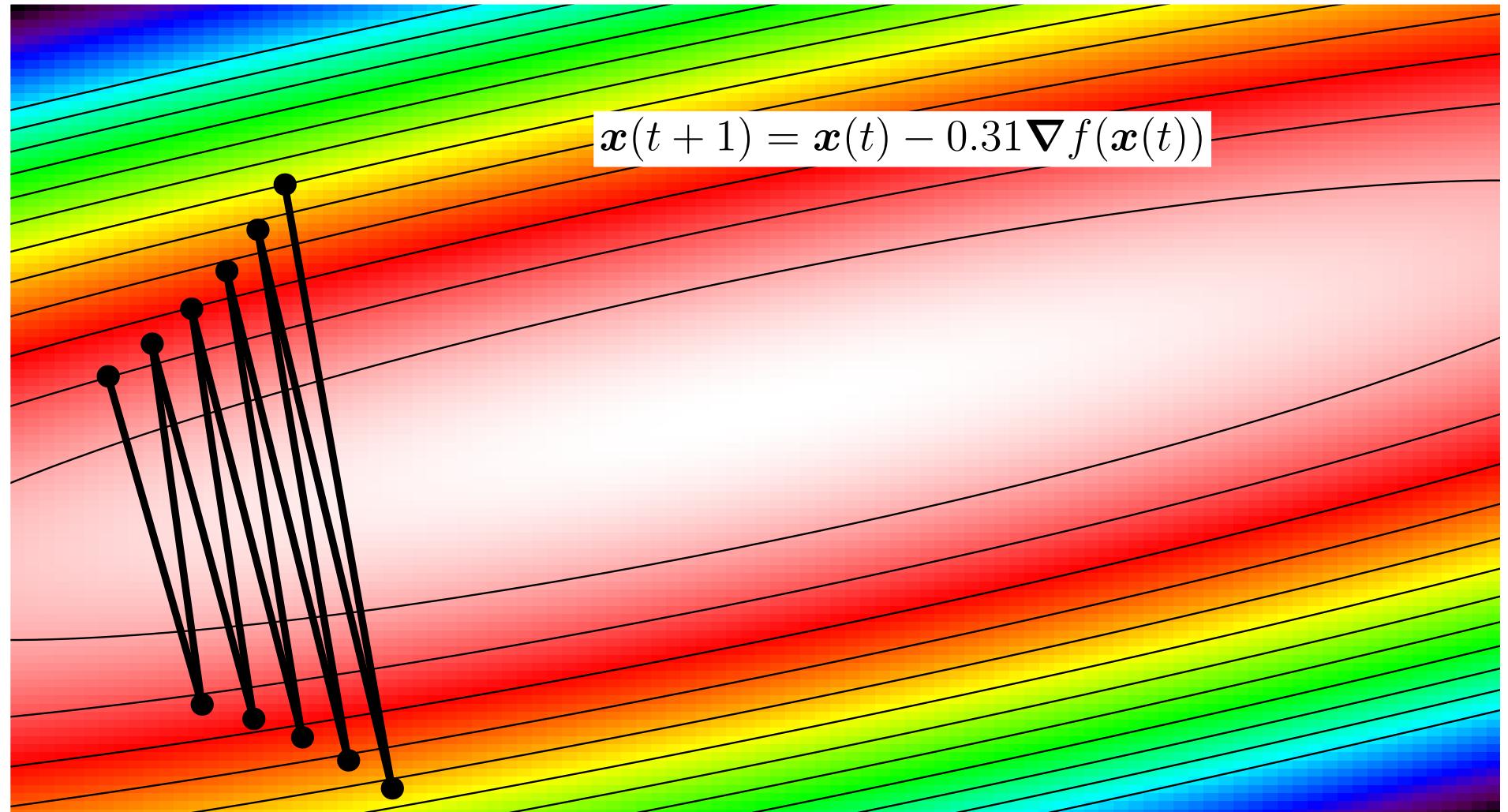
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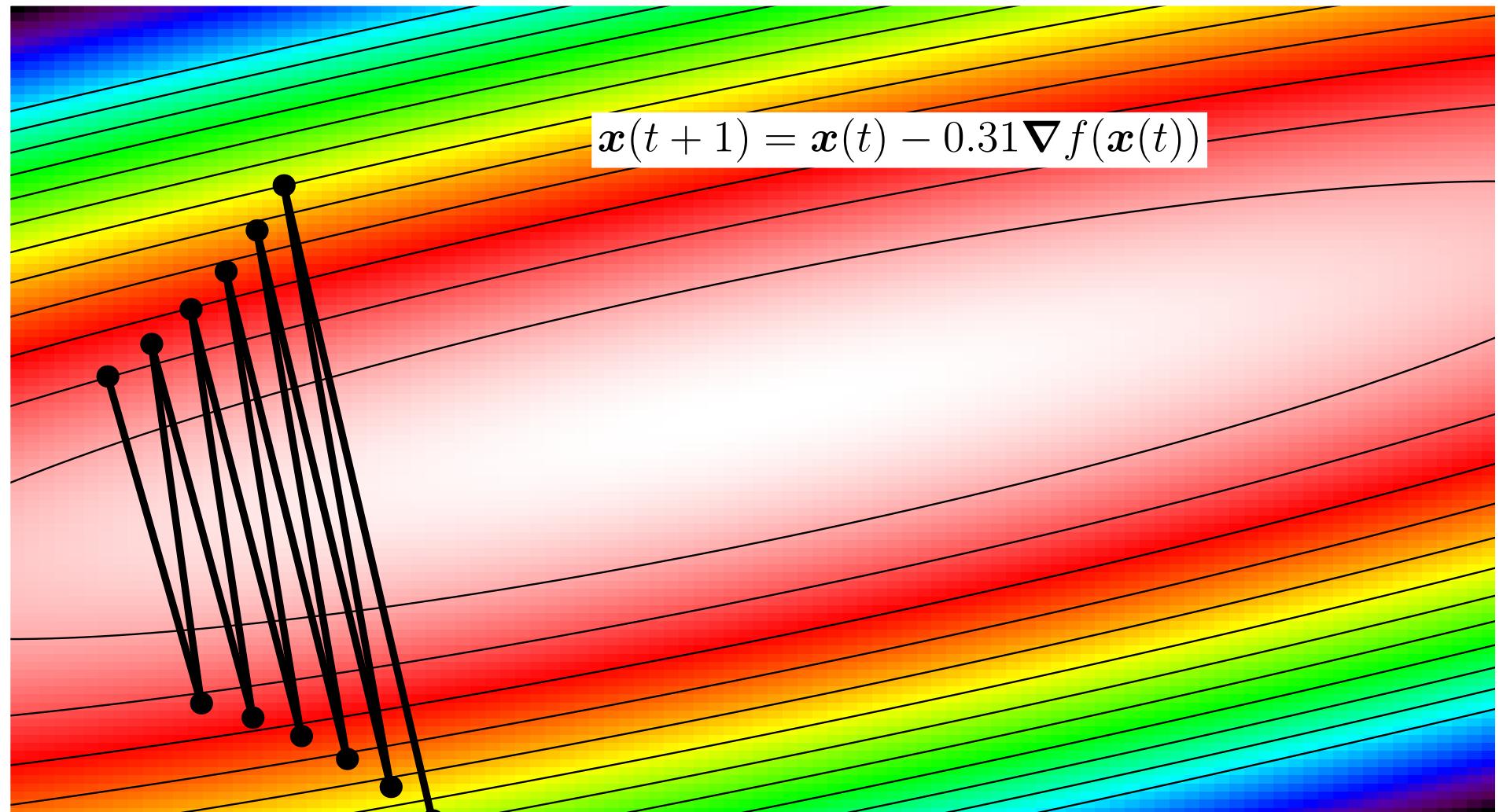
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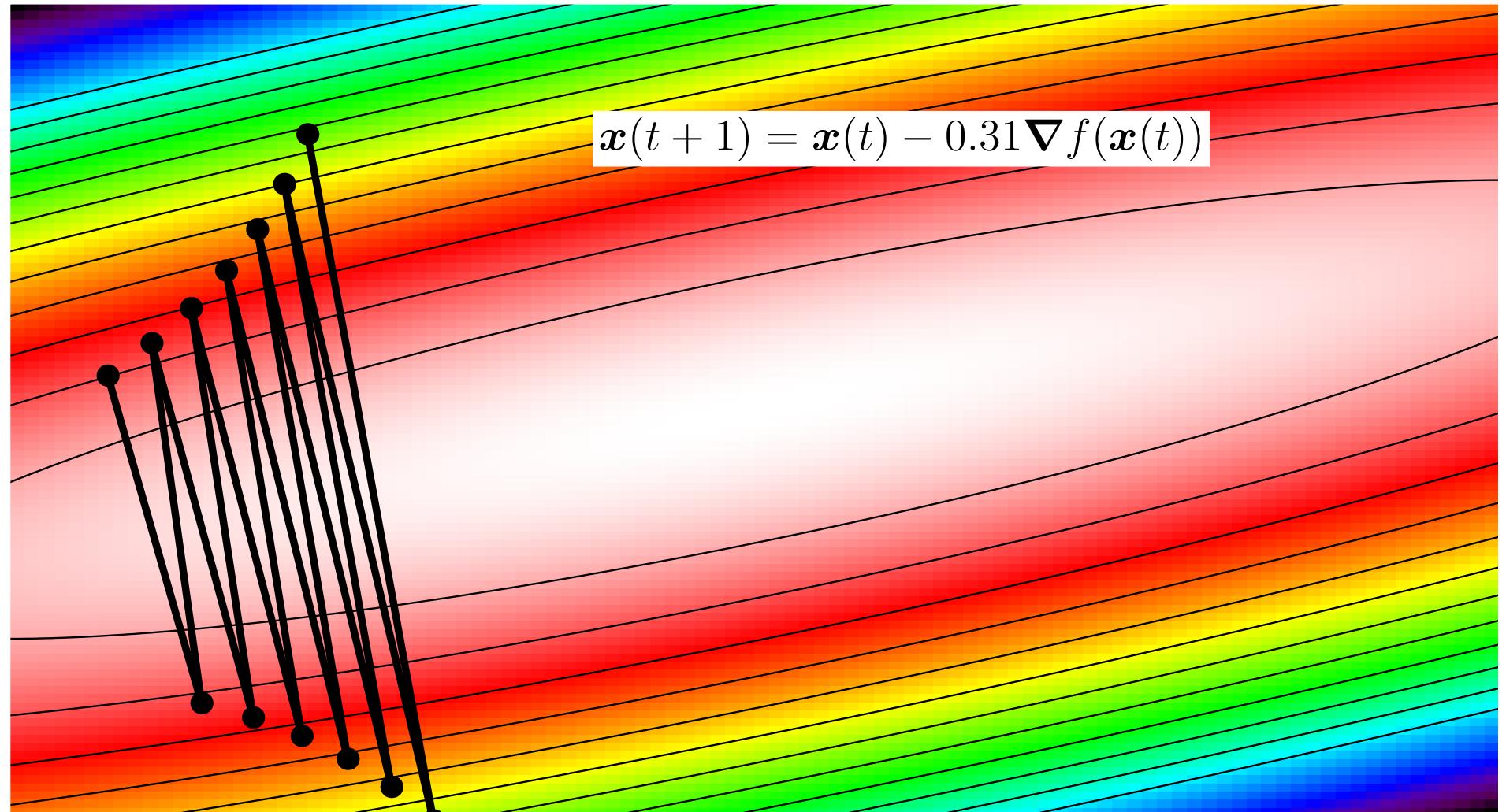
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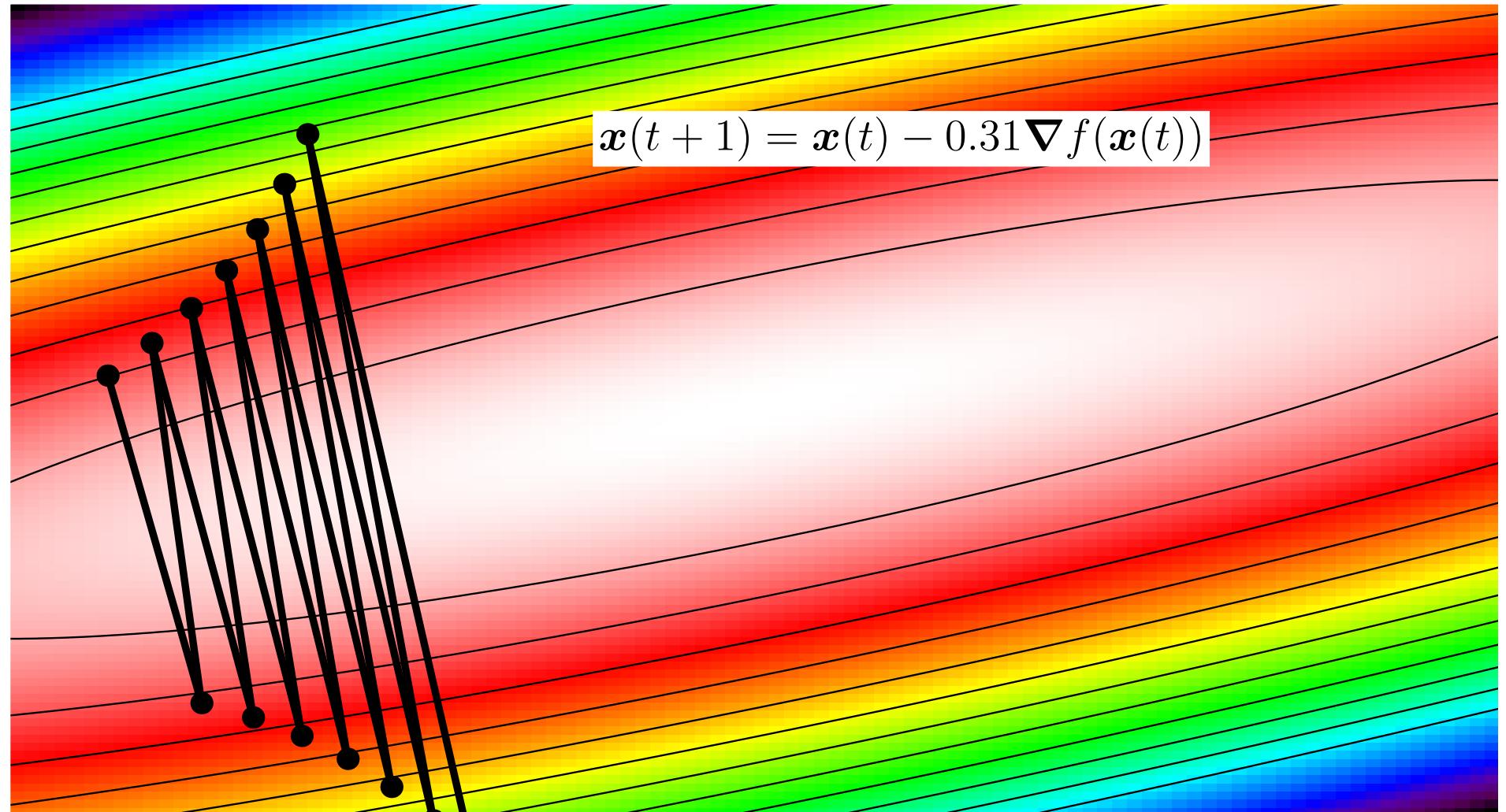
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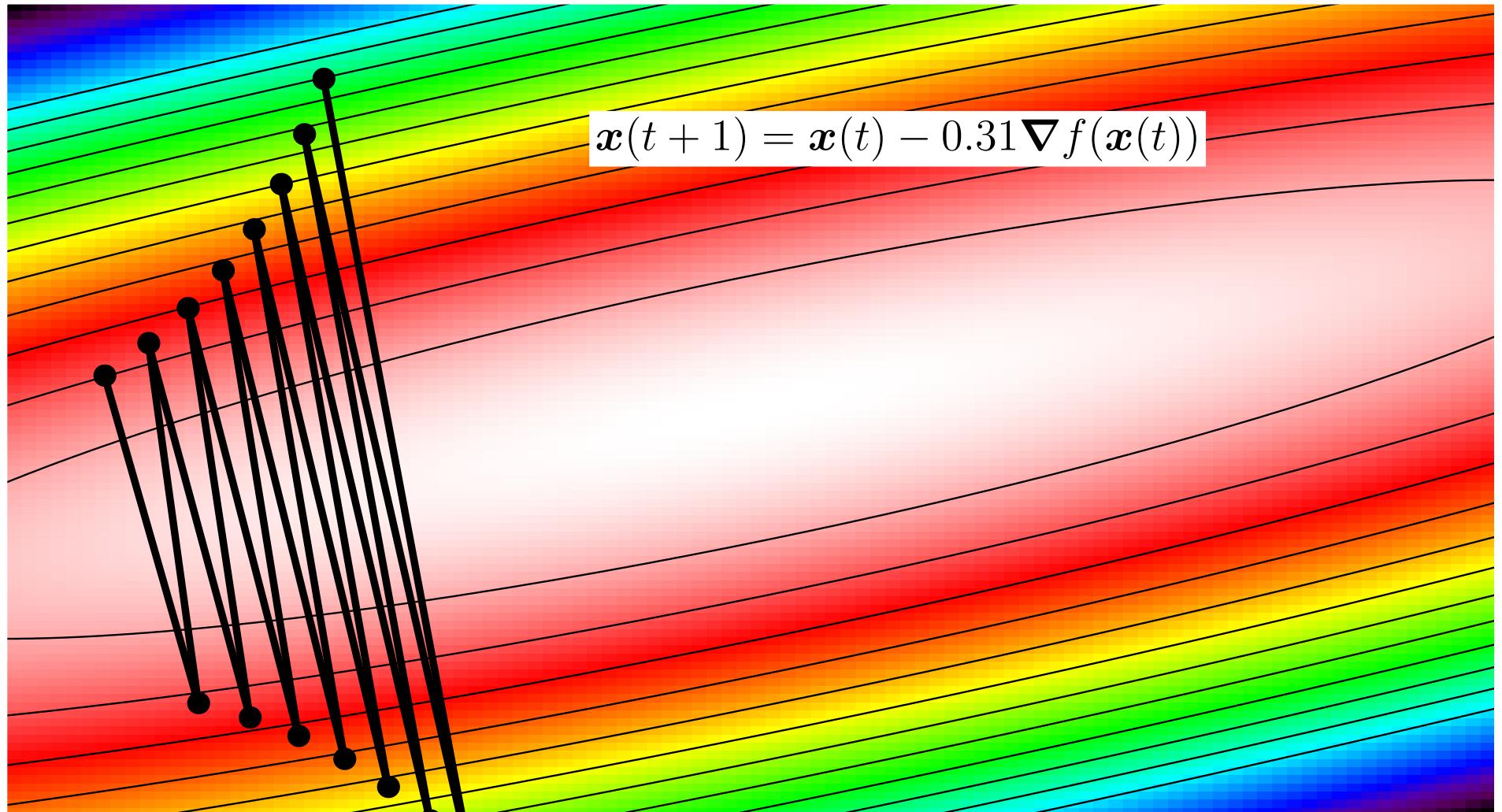
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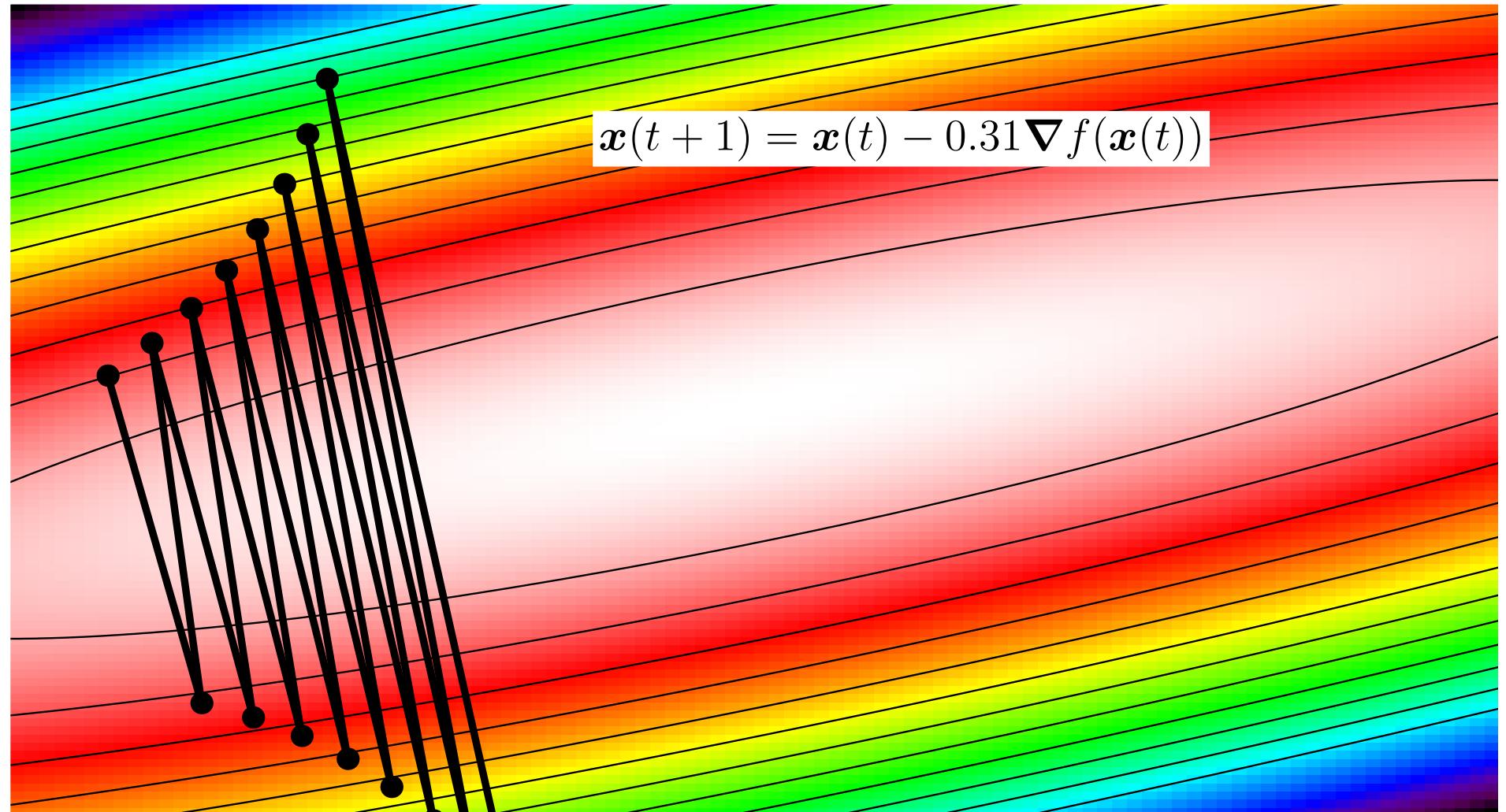
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# Avoiding Divergence

- We saw in the last lecture that gradient descent can actually diverge from a local optimum if you have a too big step size
- If we use too large a step size we quickly get NaN errors
- If we only use SGD the step size is determined by the largest eigenvalue of the Hessian

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# Momentum

- In high dimensions we zig-zag:
  - ★ stepping consistently in directions with low curvature
  - ★ jumping backwards and forwards past the minimum in directions with high curvature
- By introducing “momentum” we can increase our steps in low curvature directions and decrease it in high curvature directions

$$\mathbf{v}(t + 1) = \gamma \mathbf{v}(t) - \eta \nabla f(\mathbf{x}(t))$$

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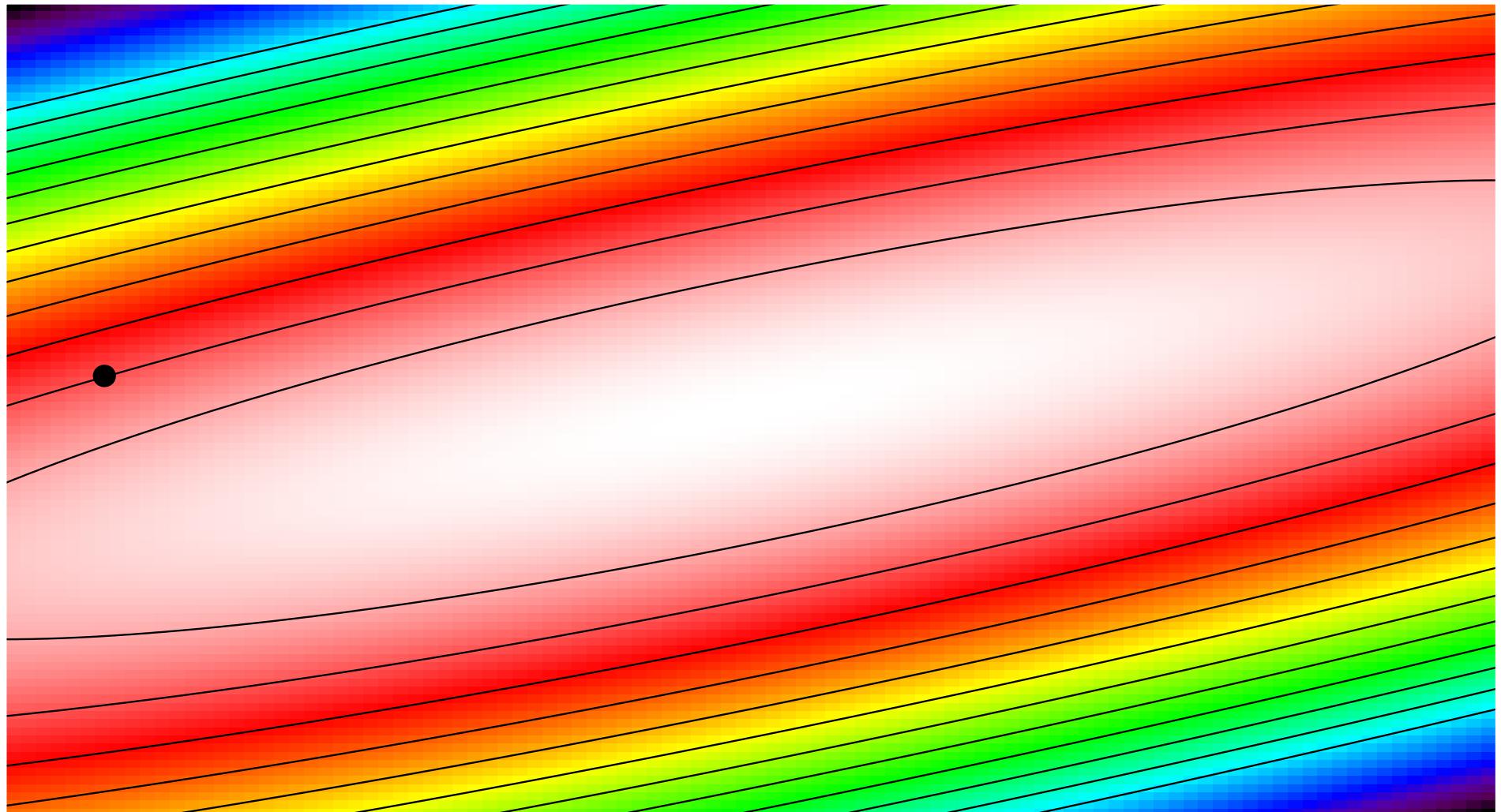
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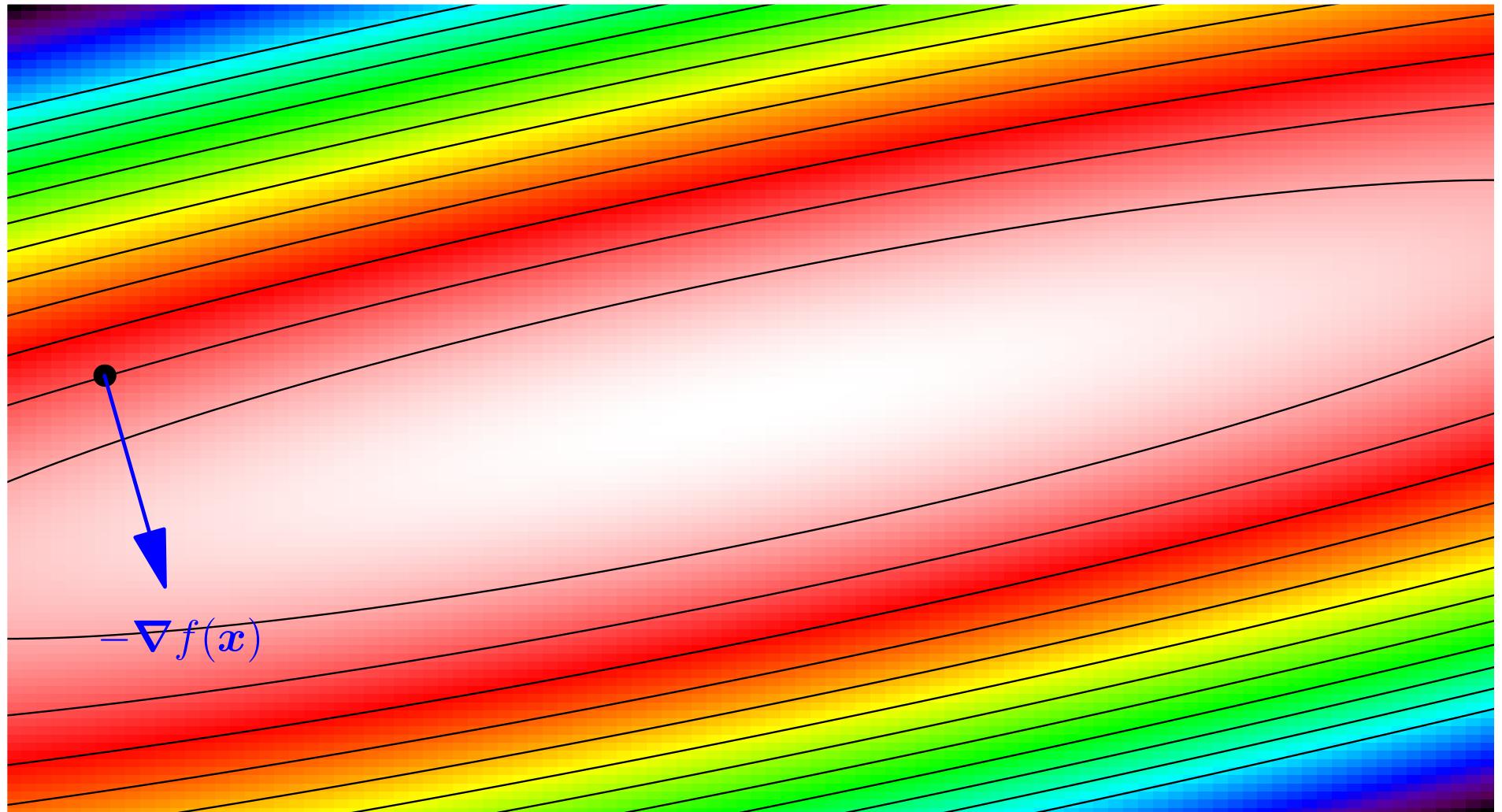
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$0 < \gamma < 1$  is a damping term

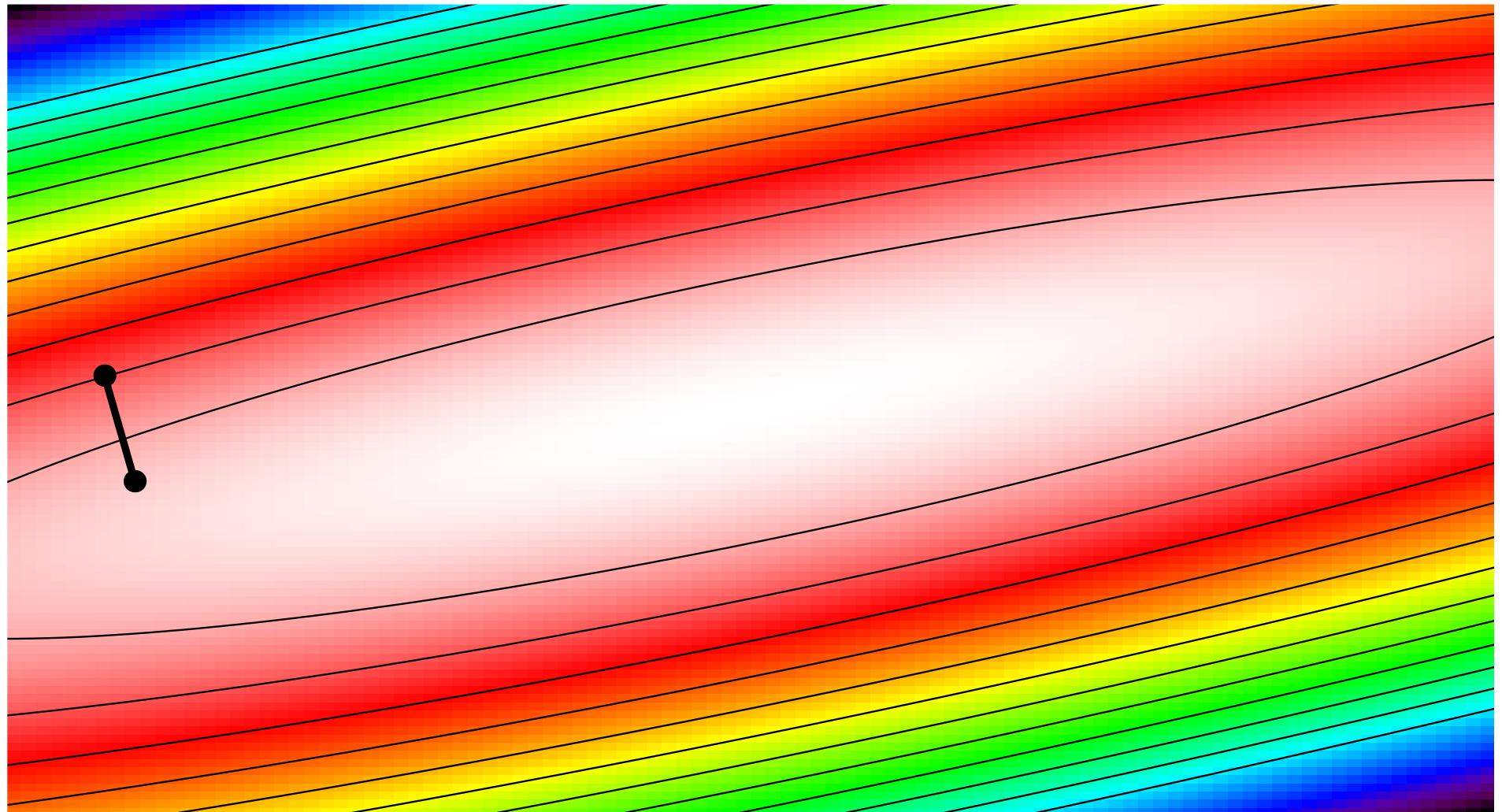
# Gradient Descent with Momentum



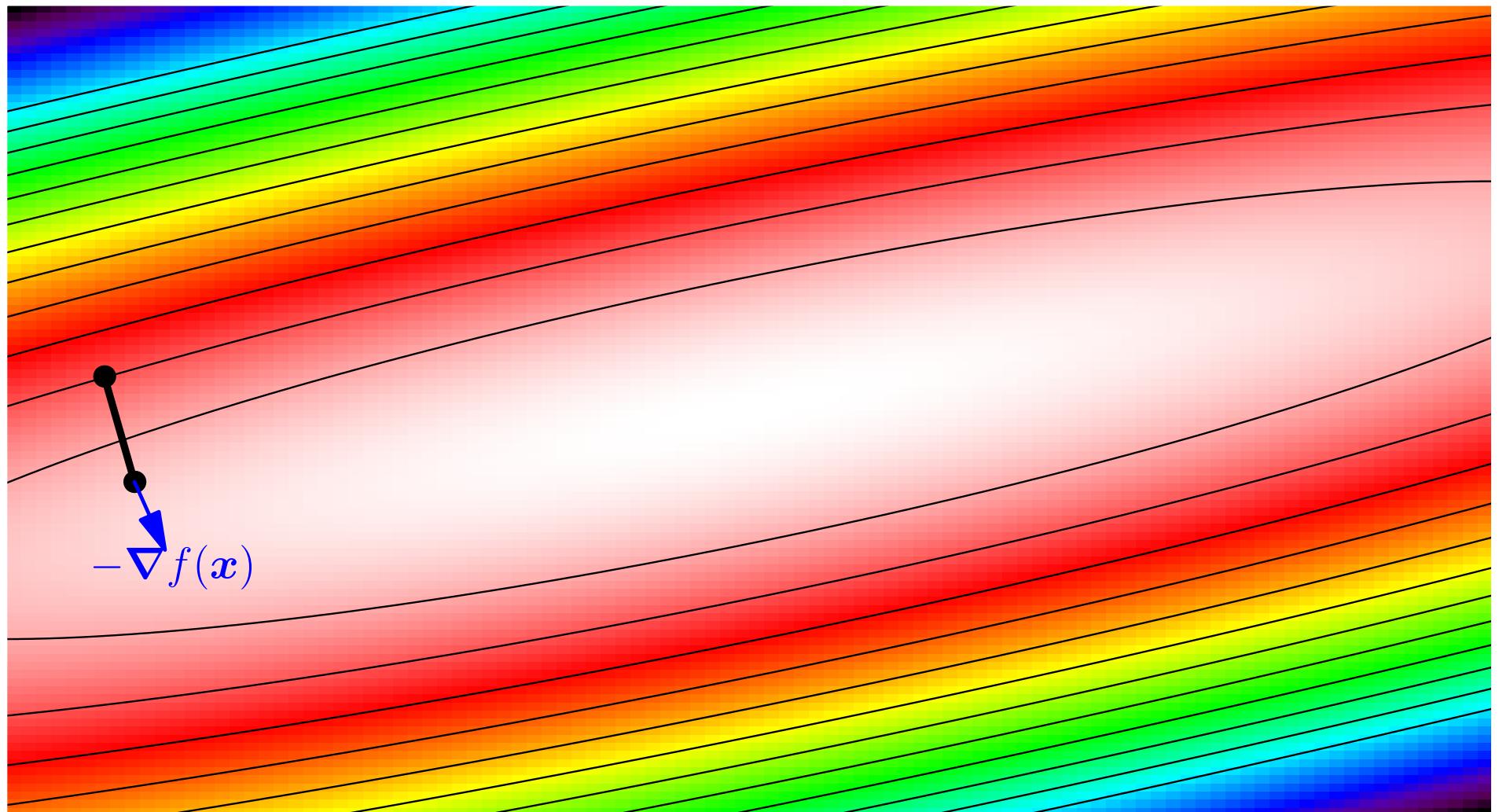
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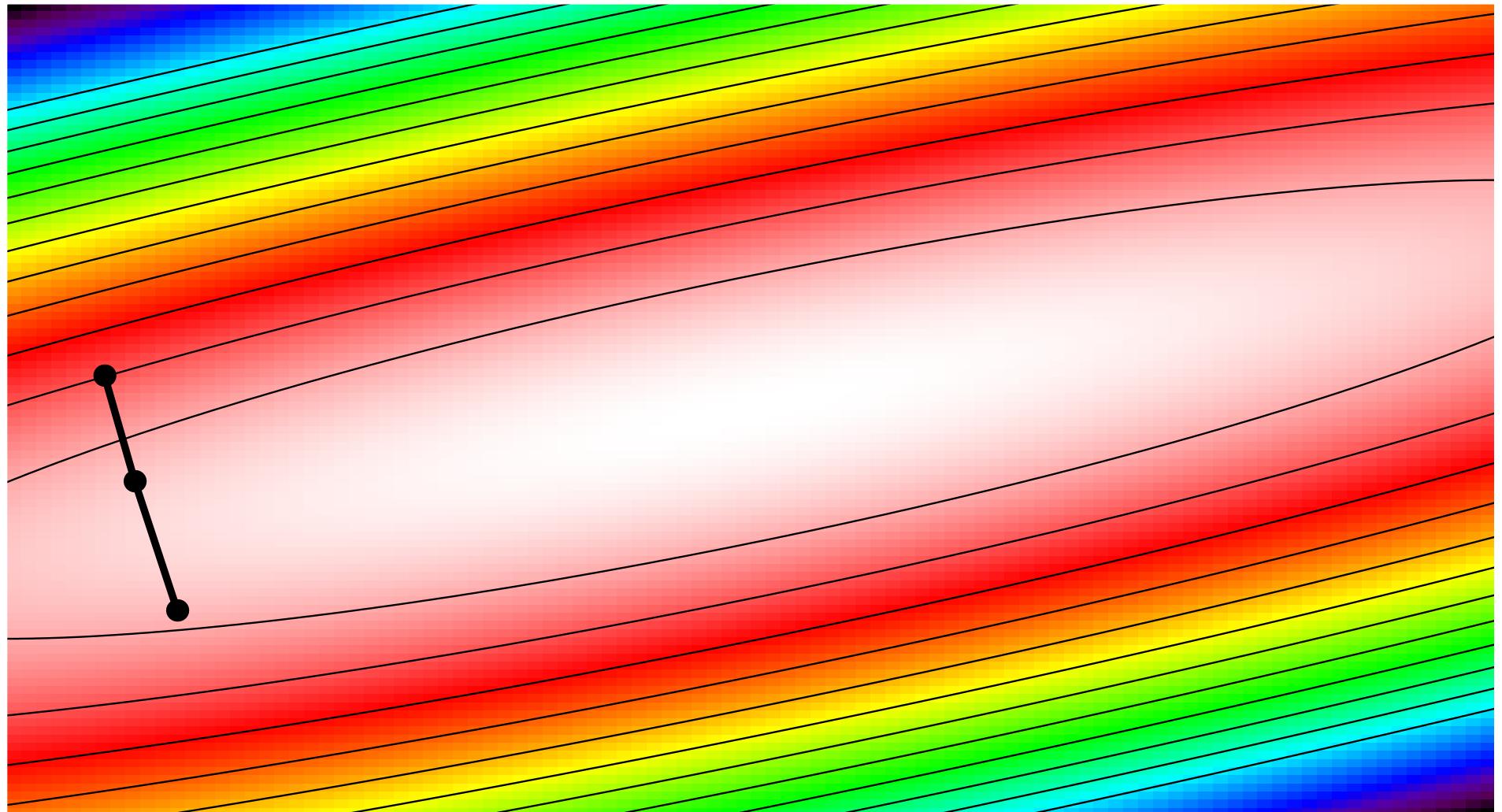
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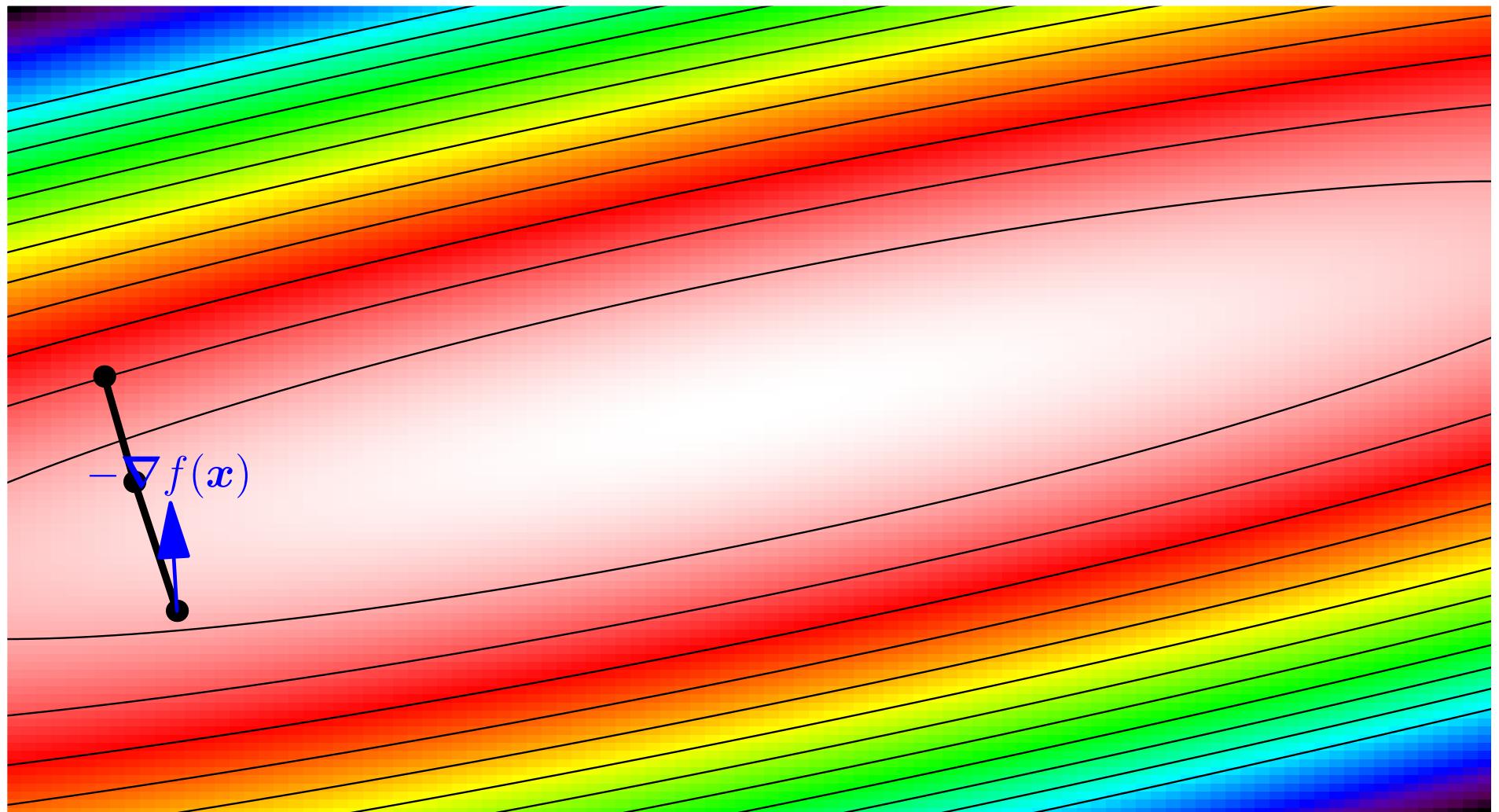
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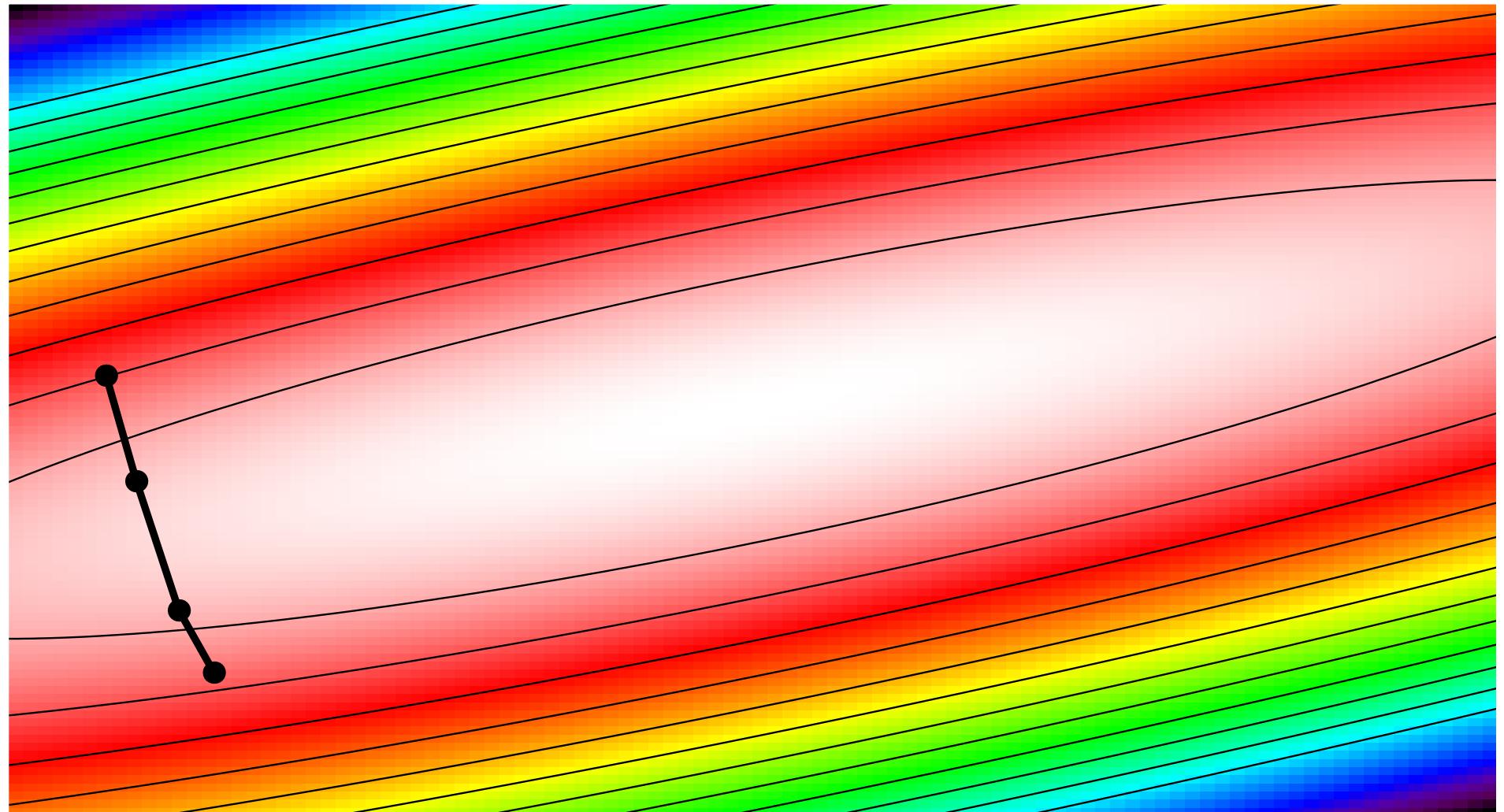
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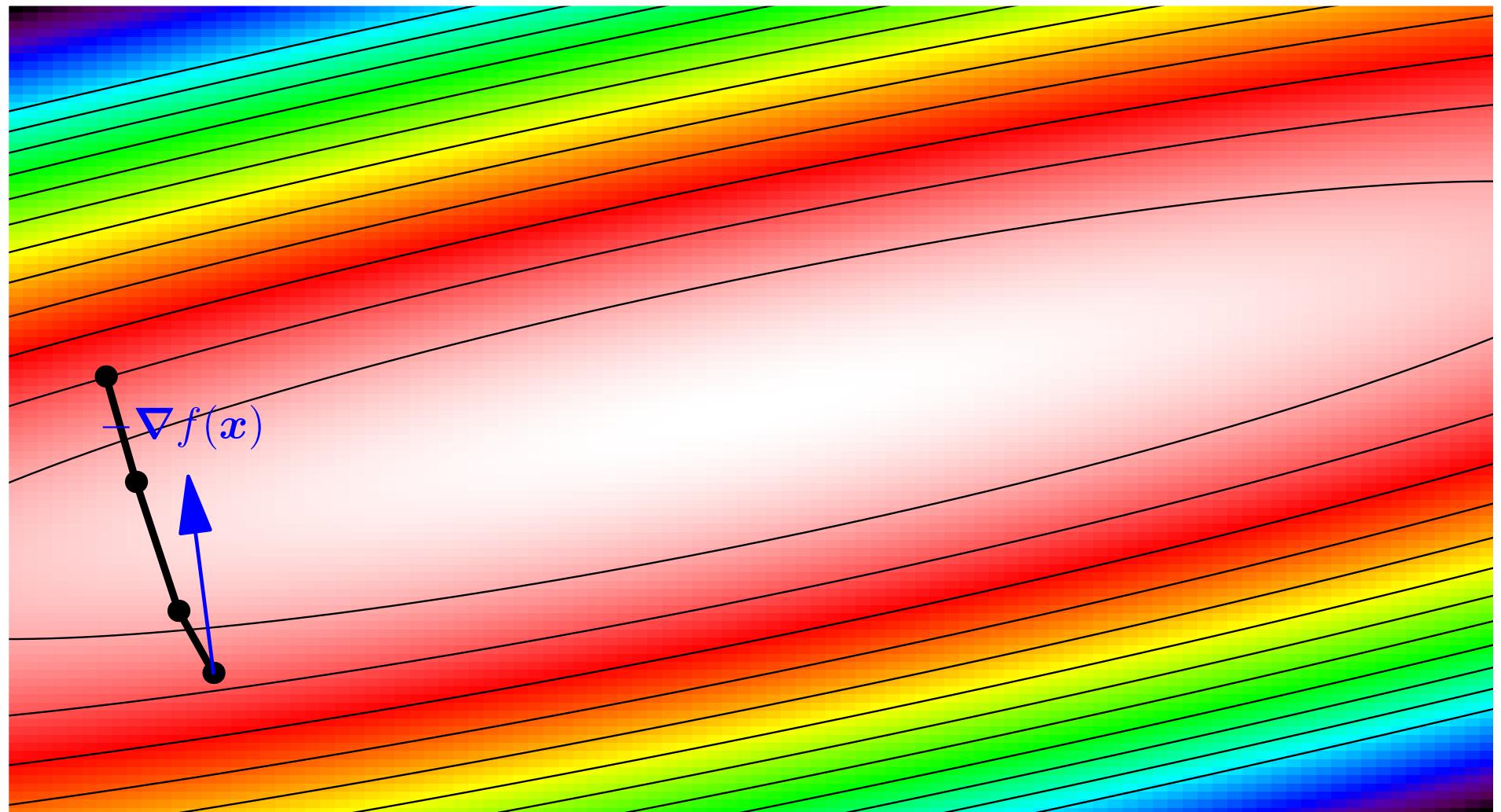
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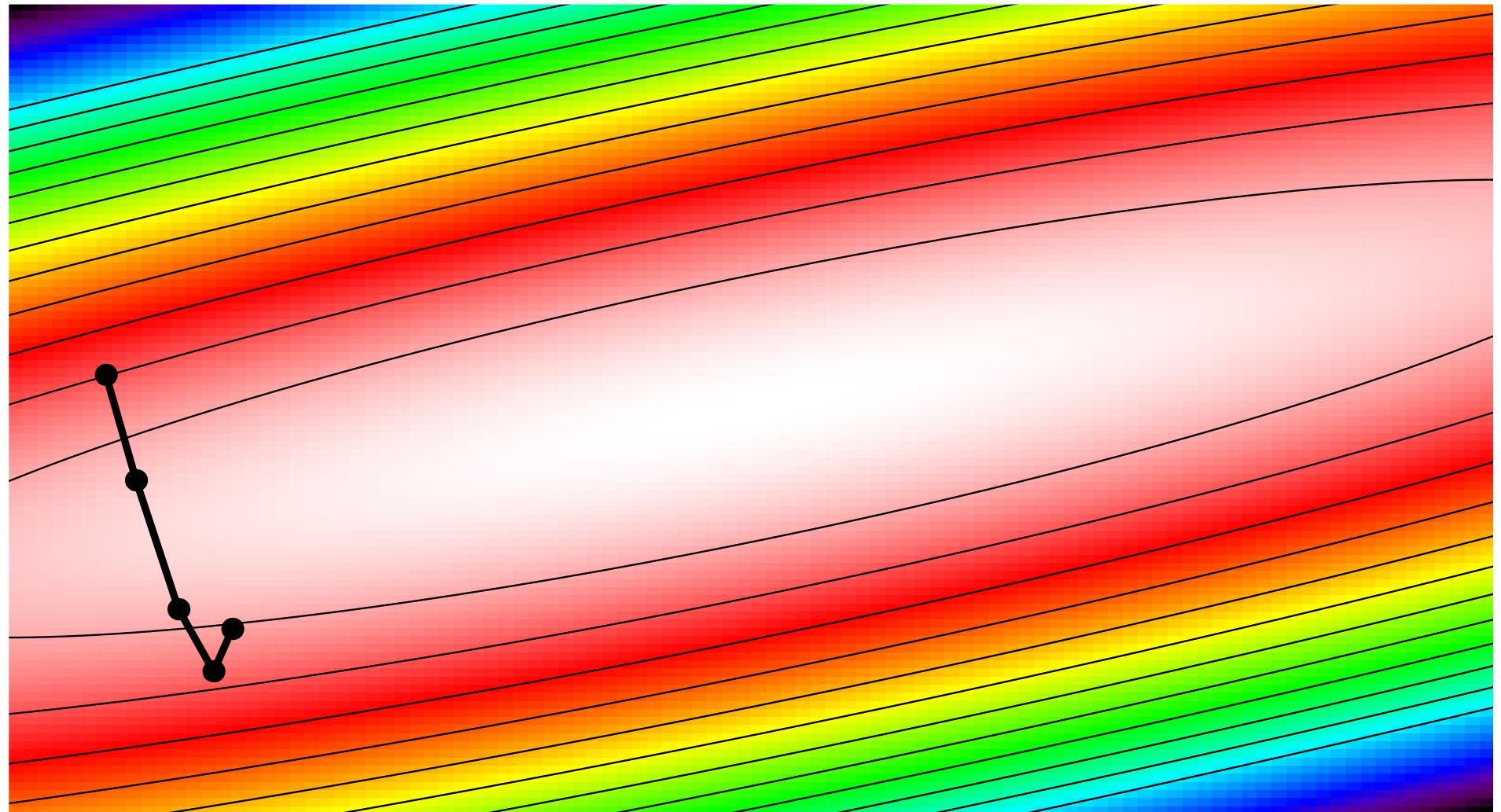
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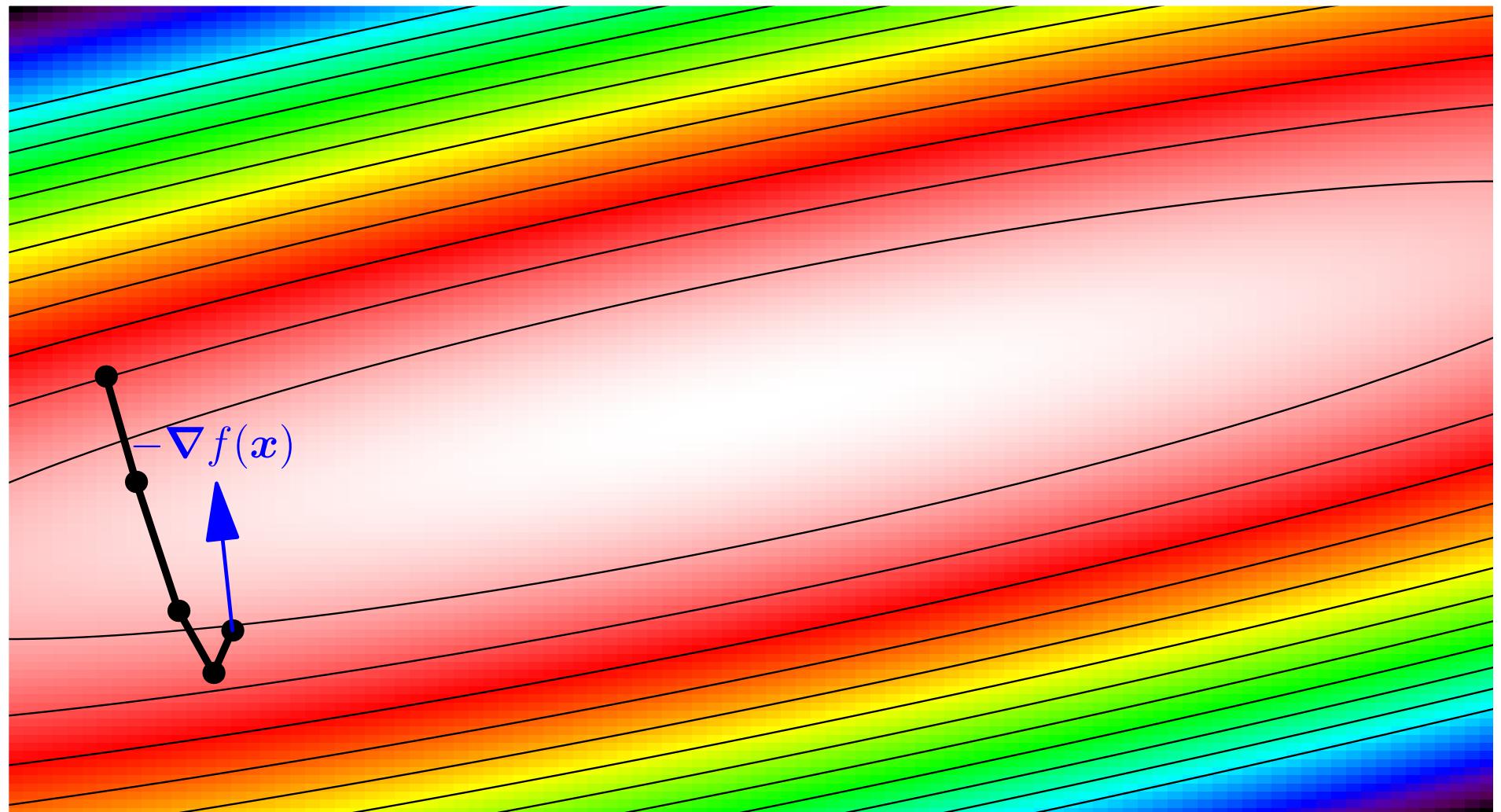
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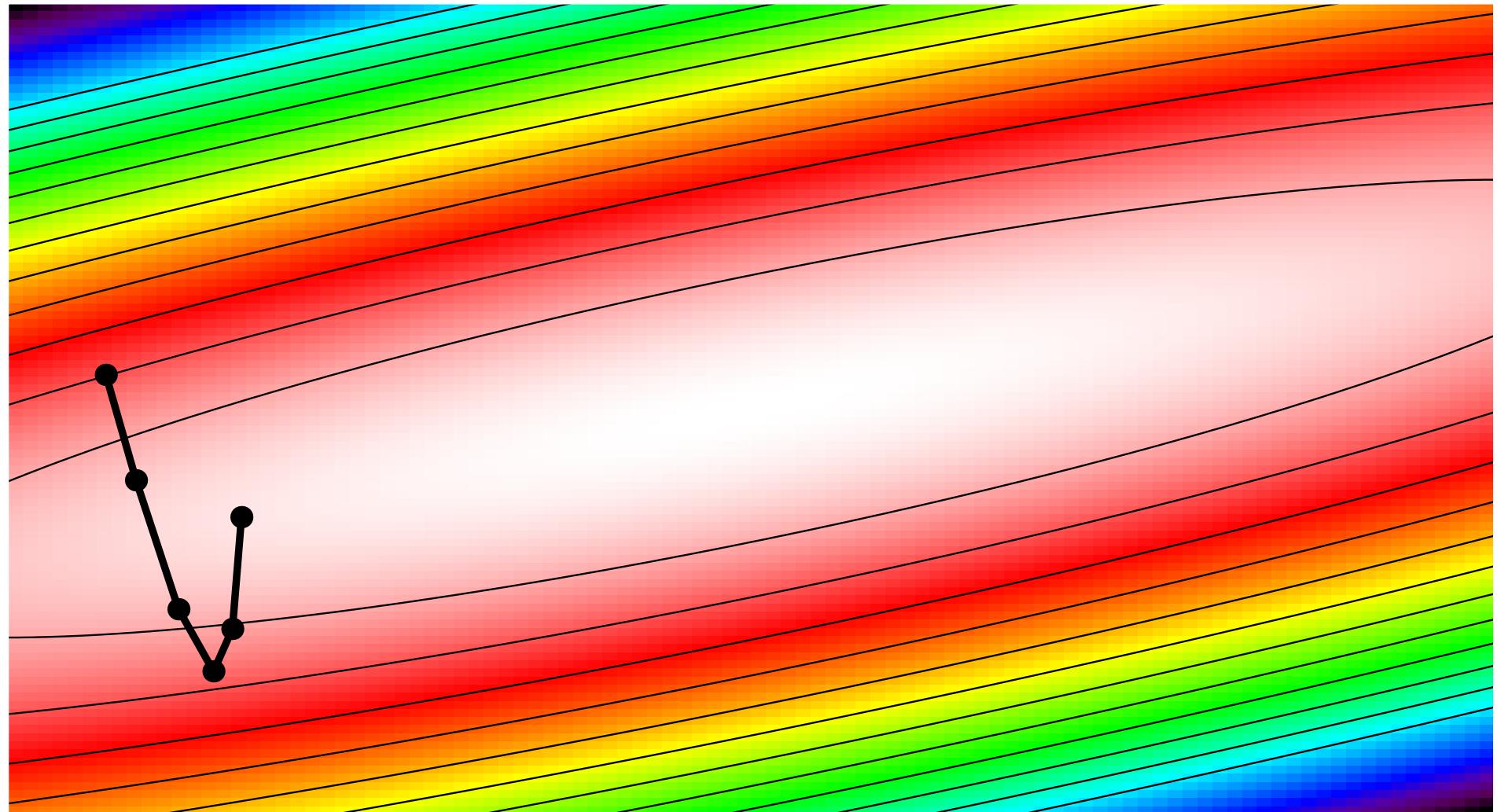
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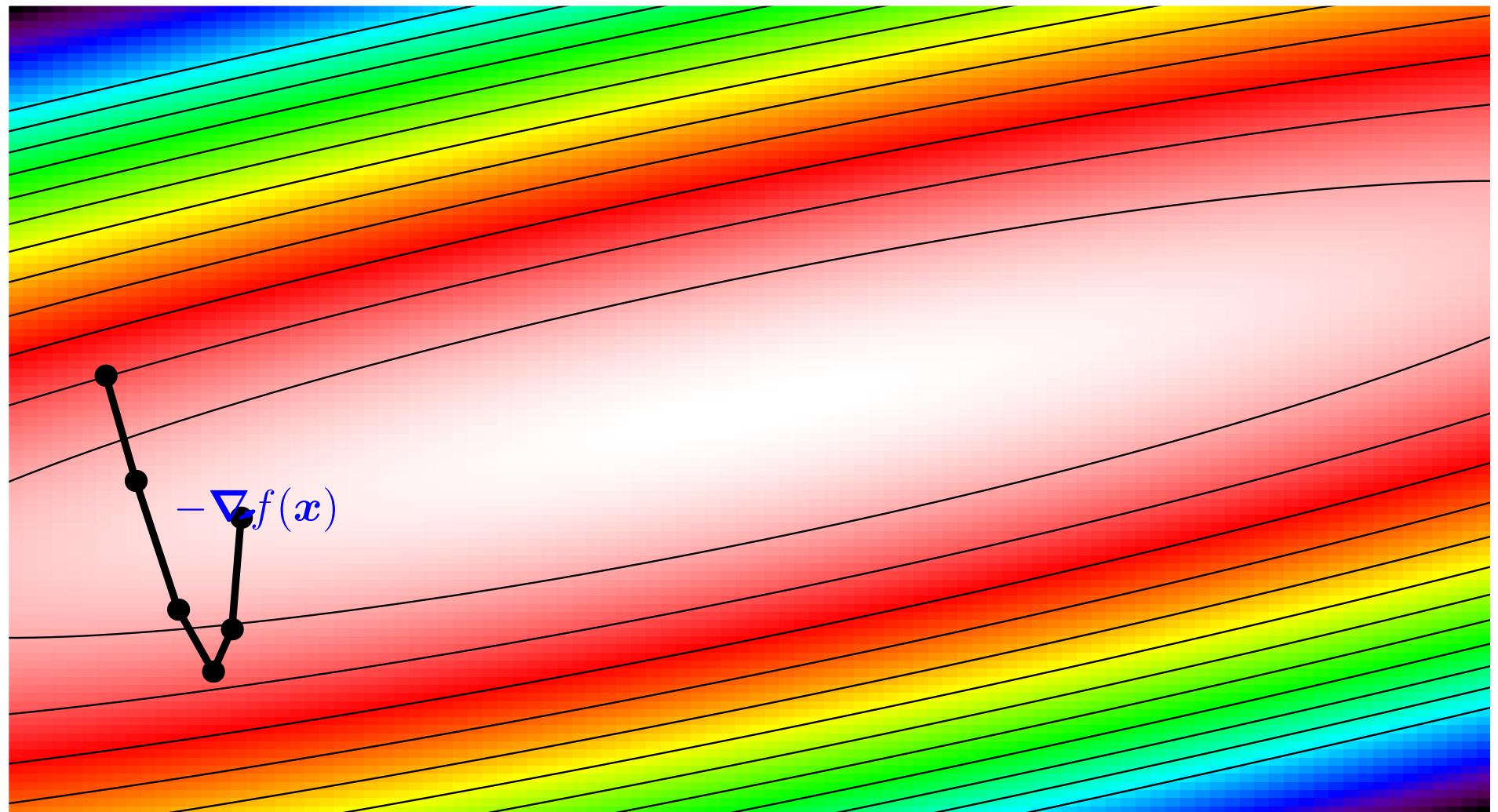
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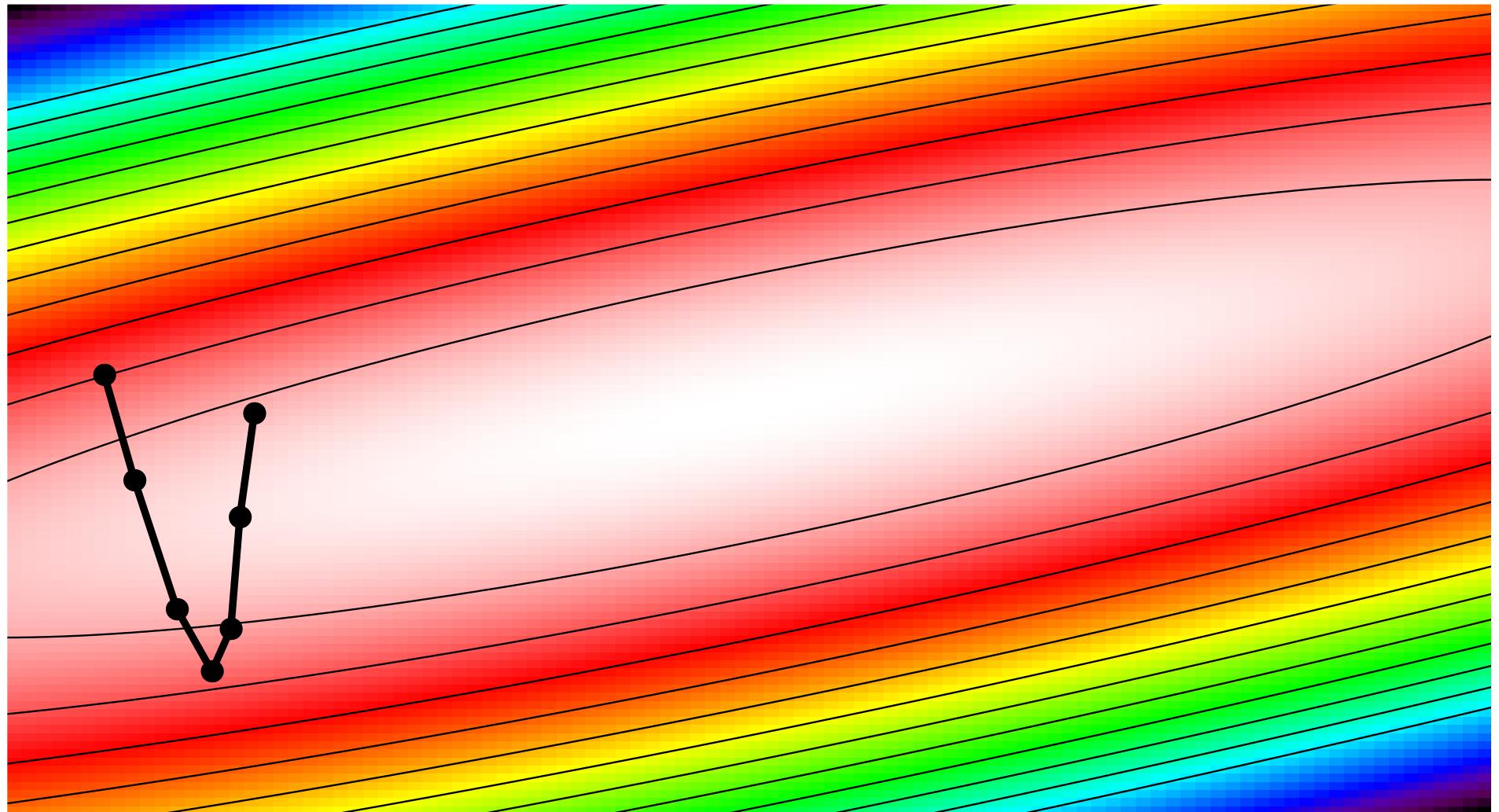
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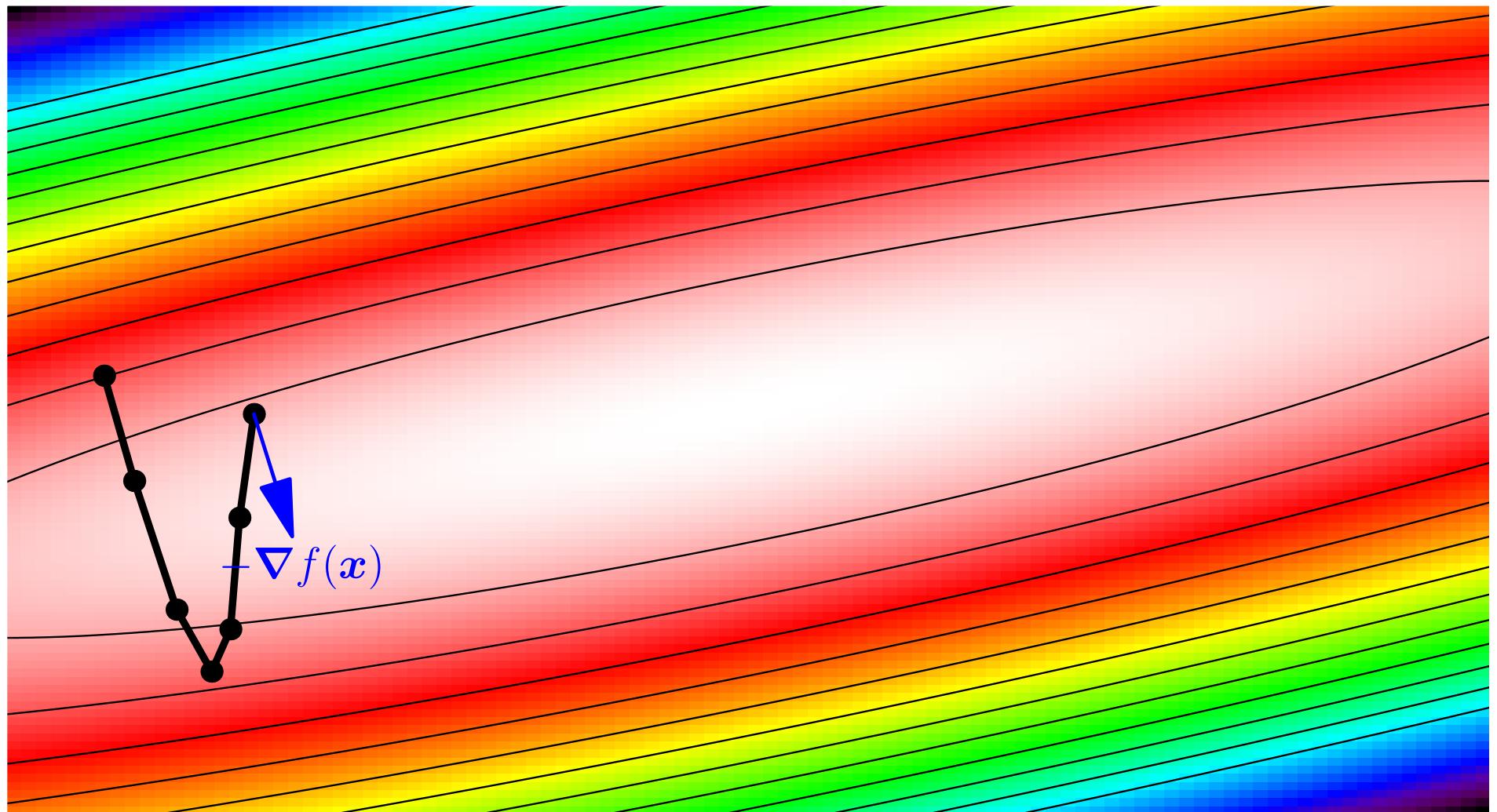
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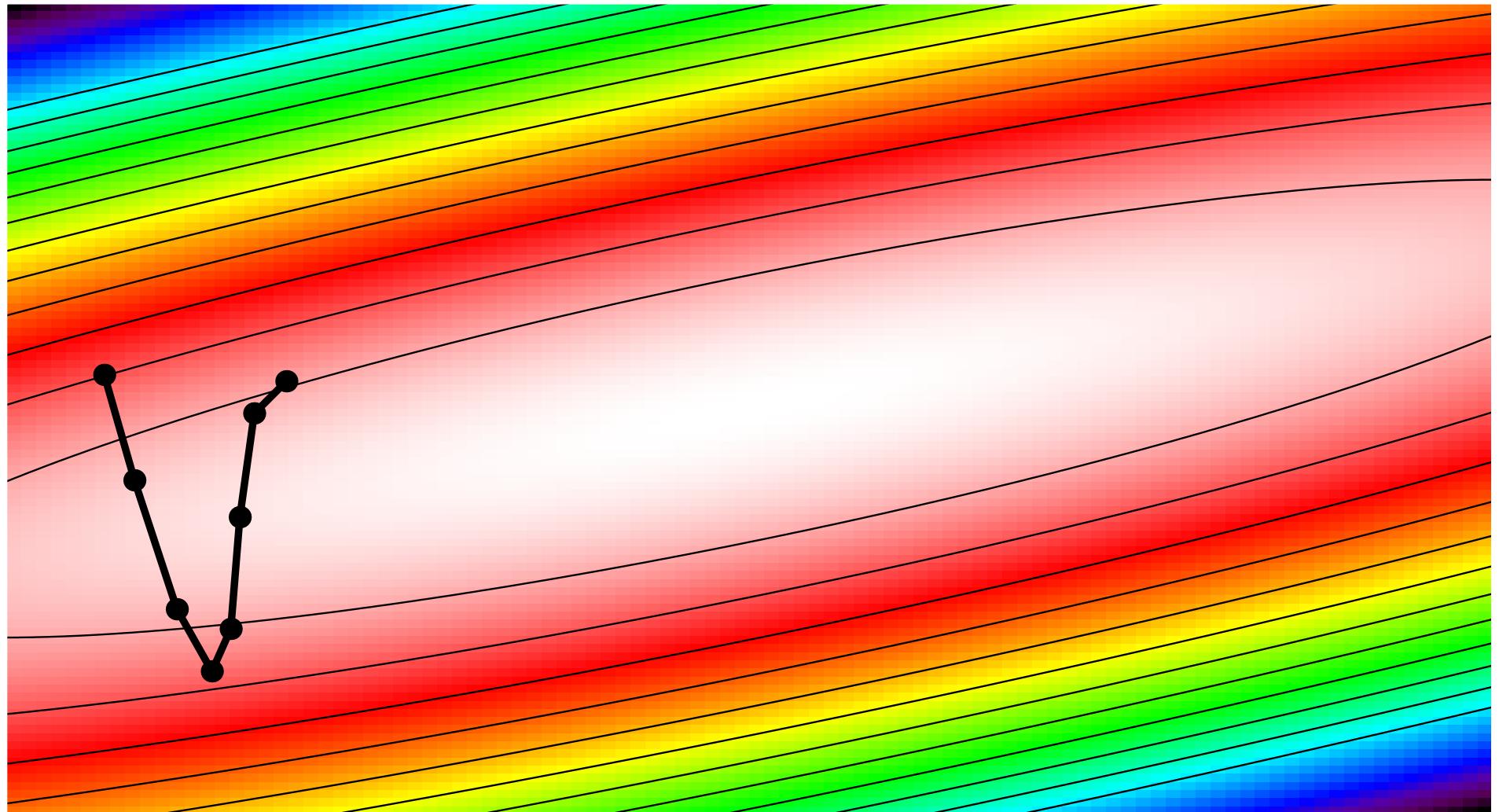
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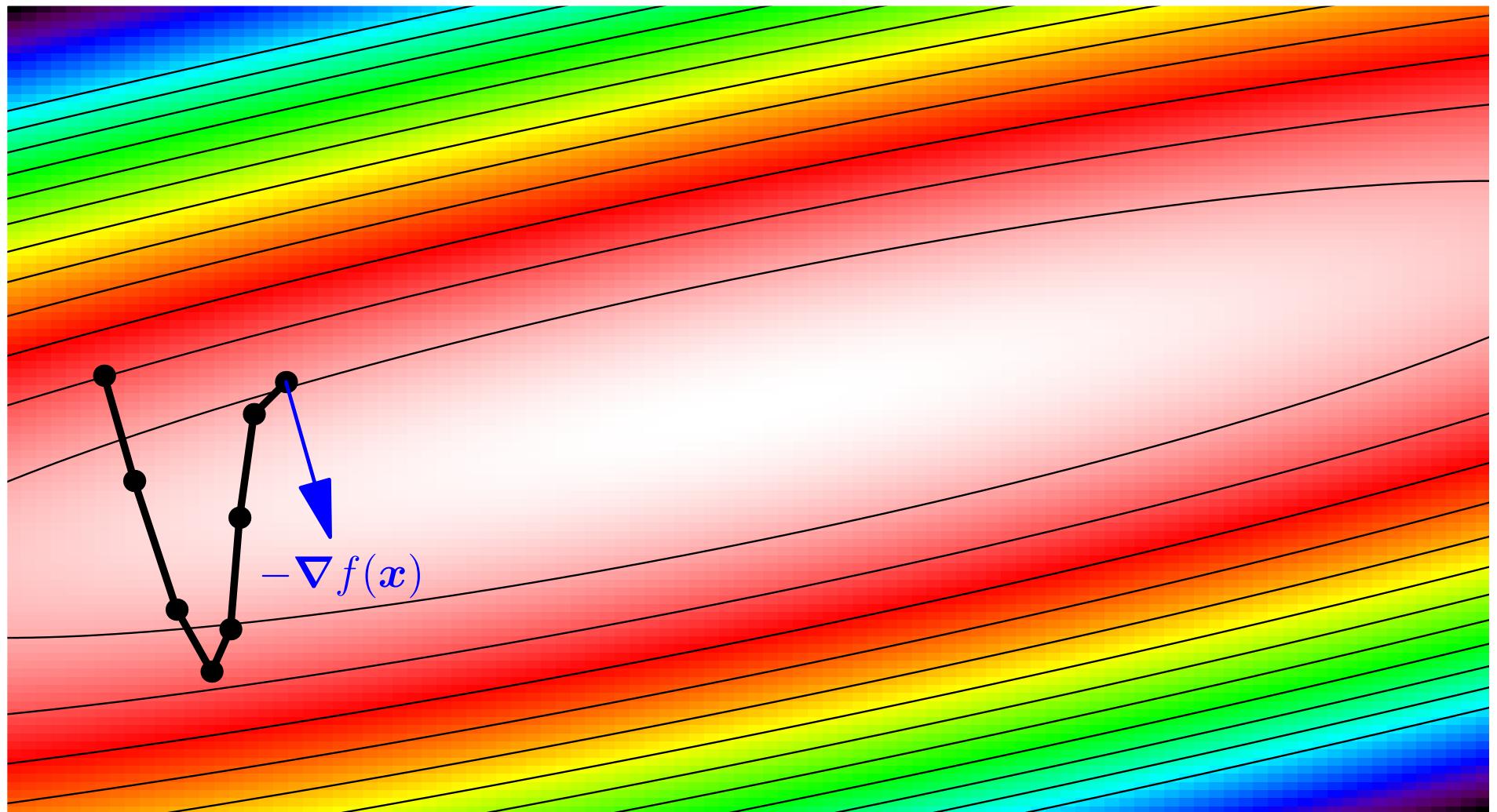
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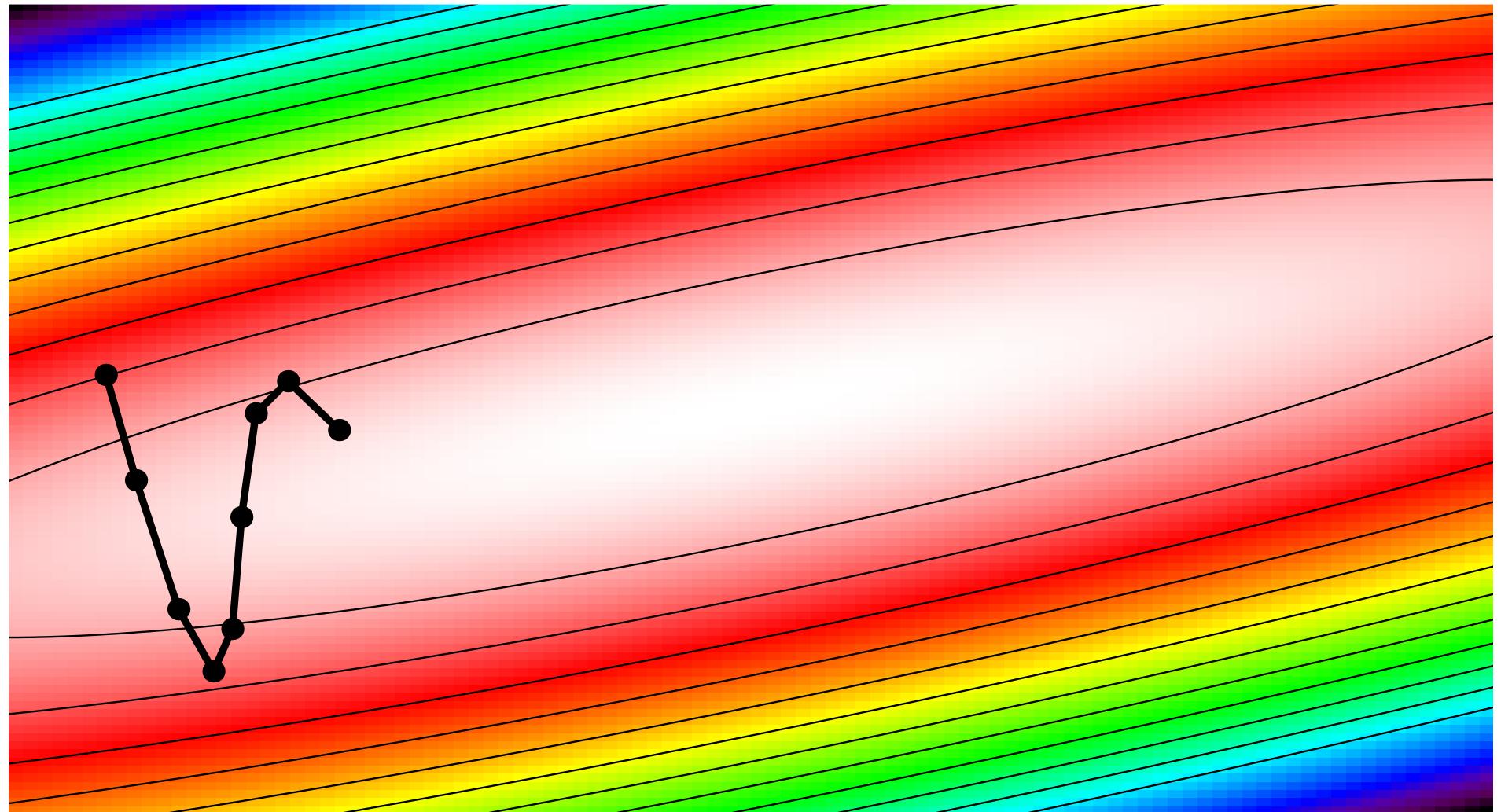
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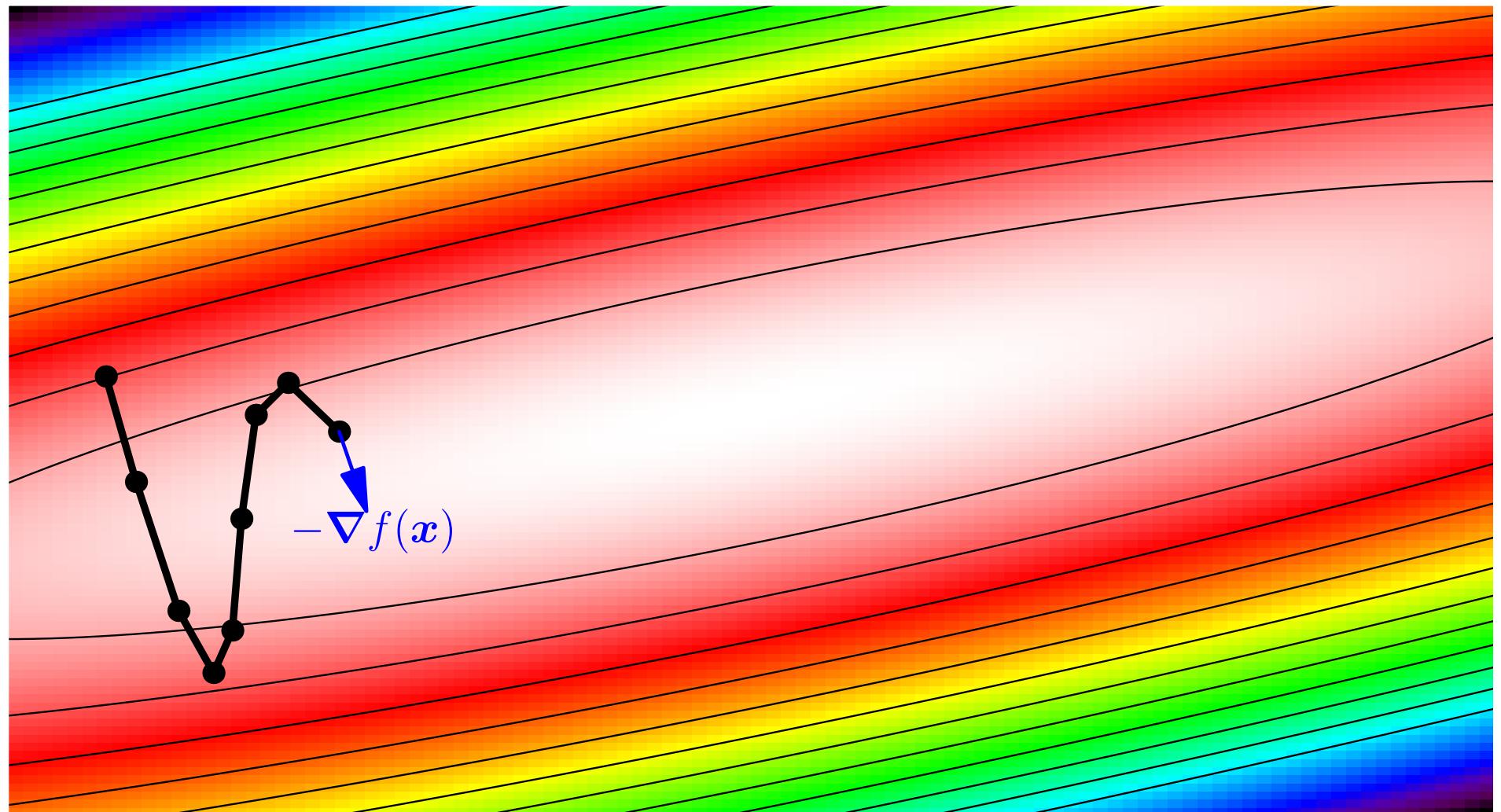
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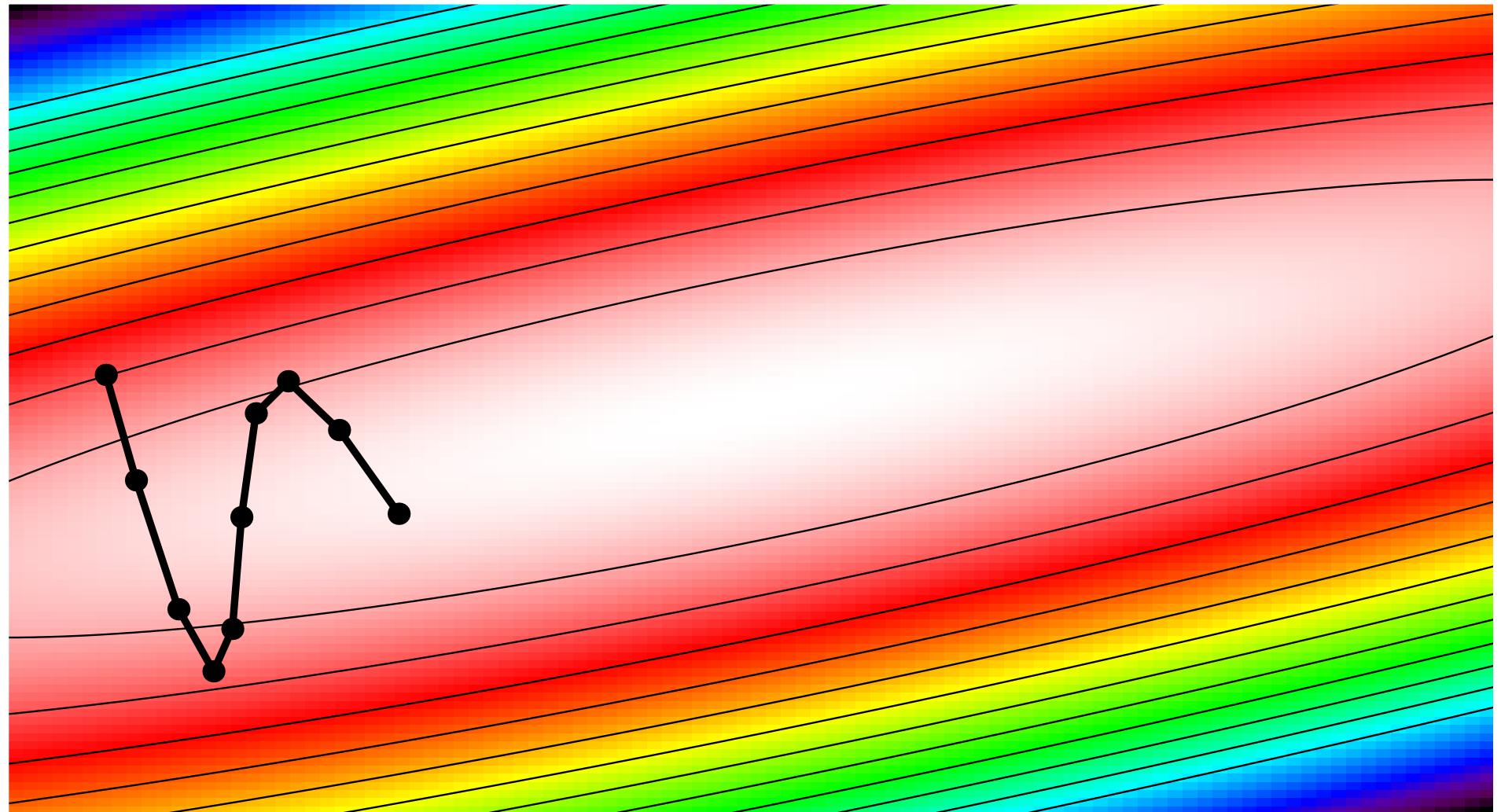
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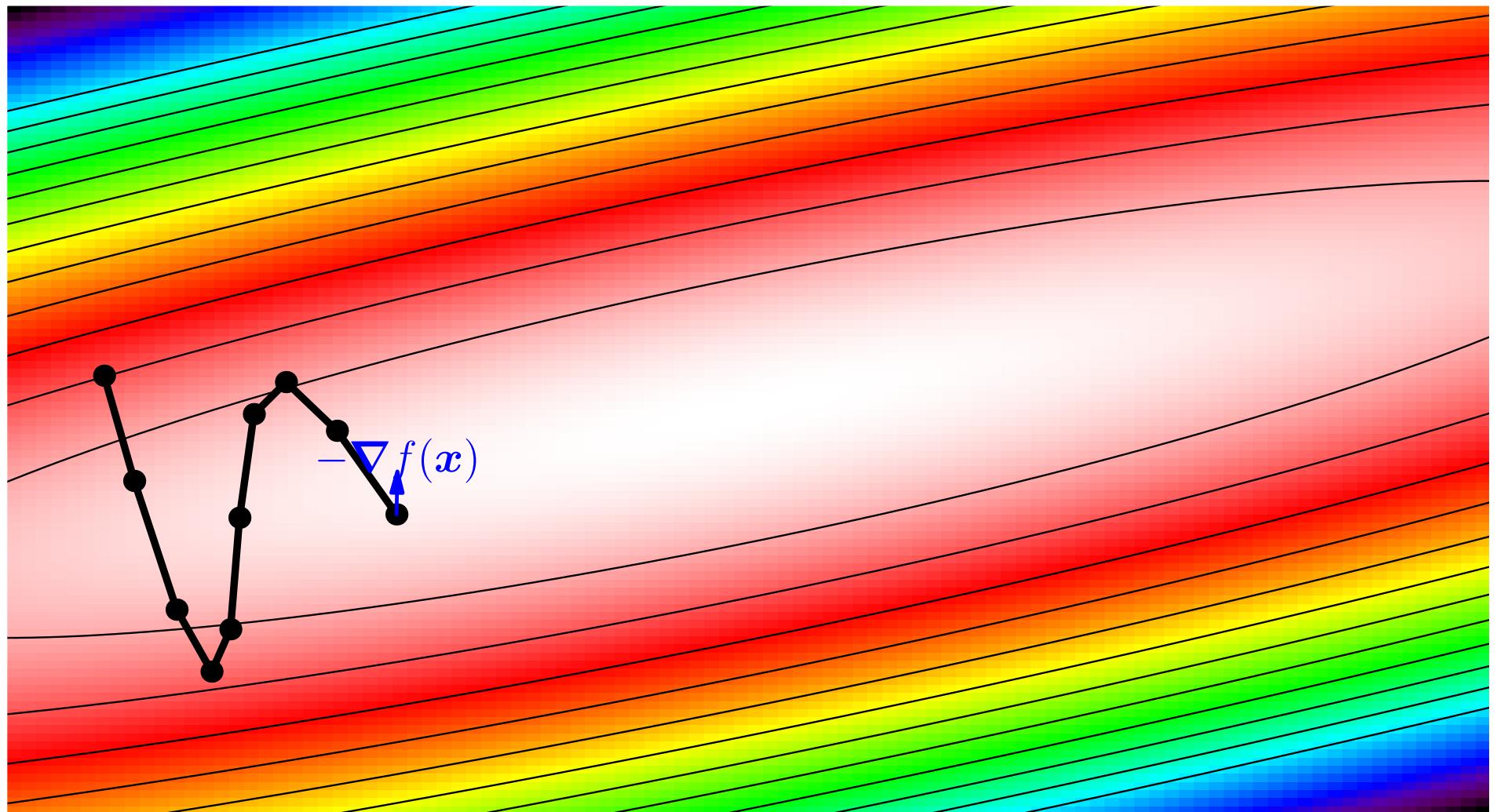
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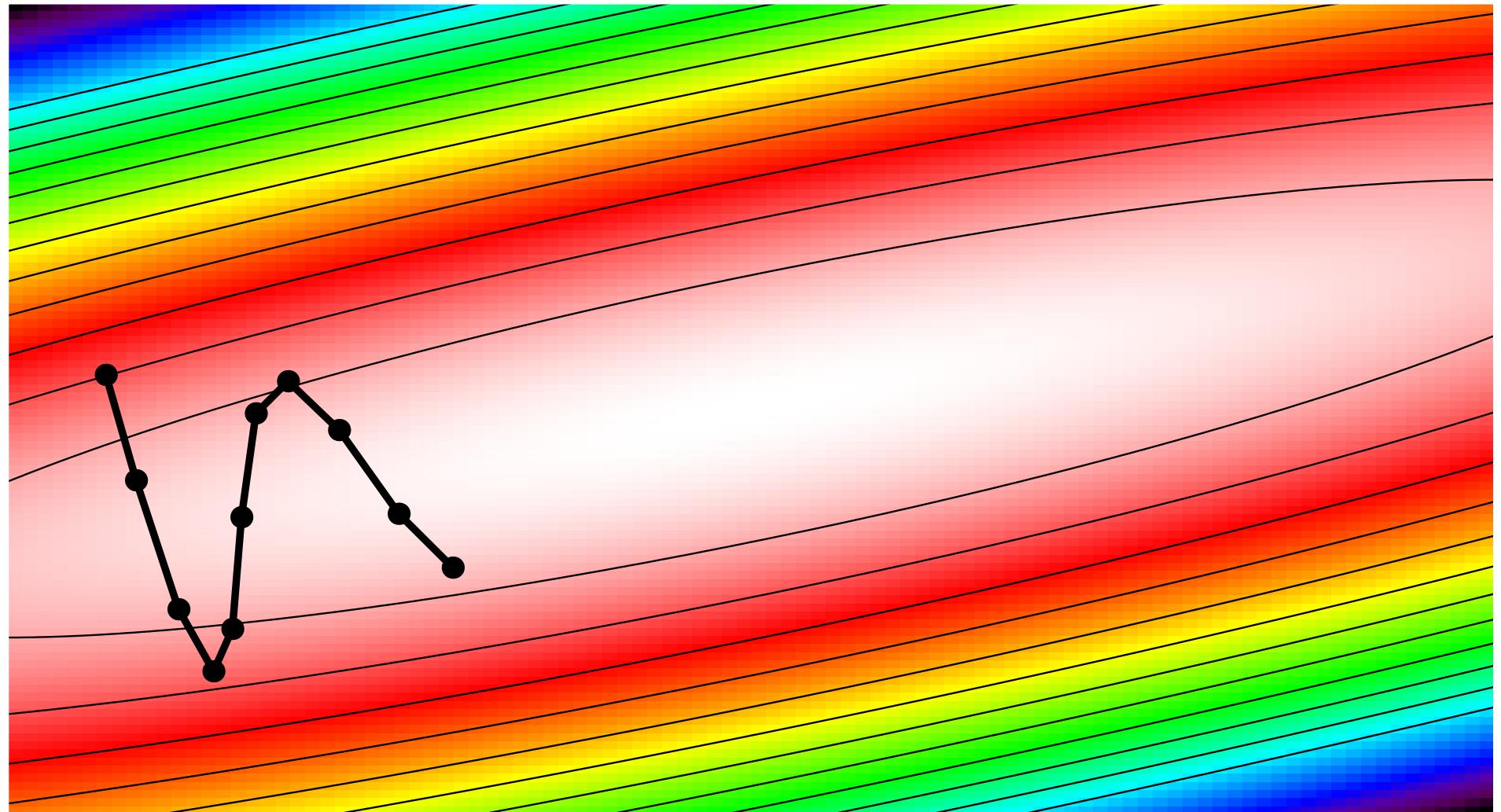
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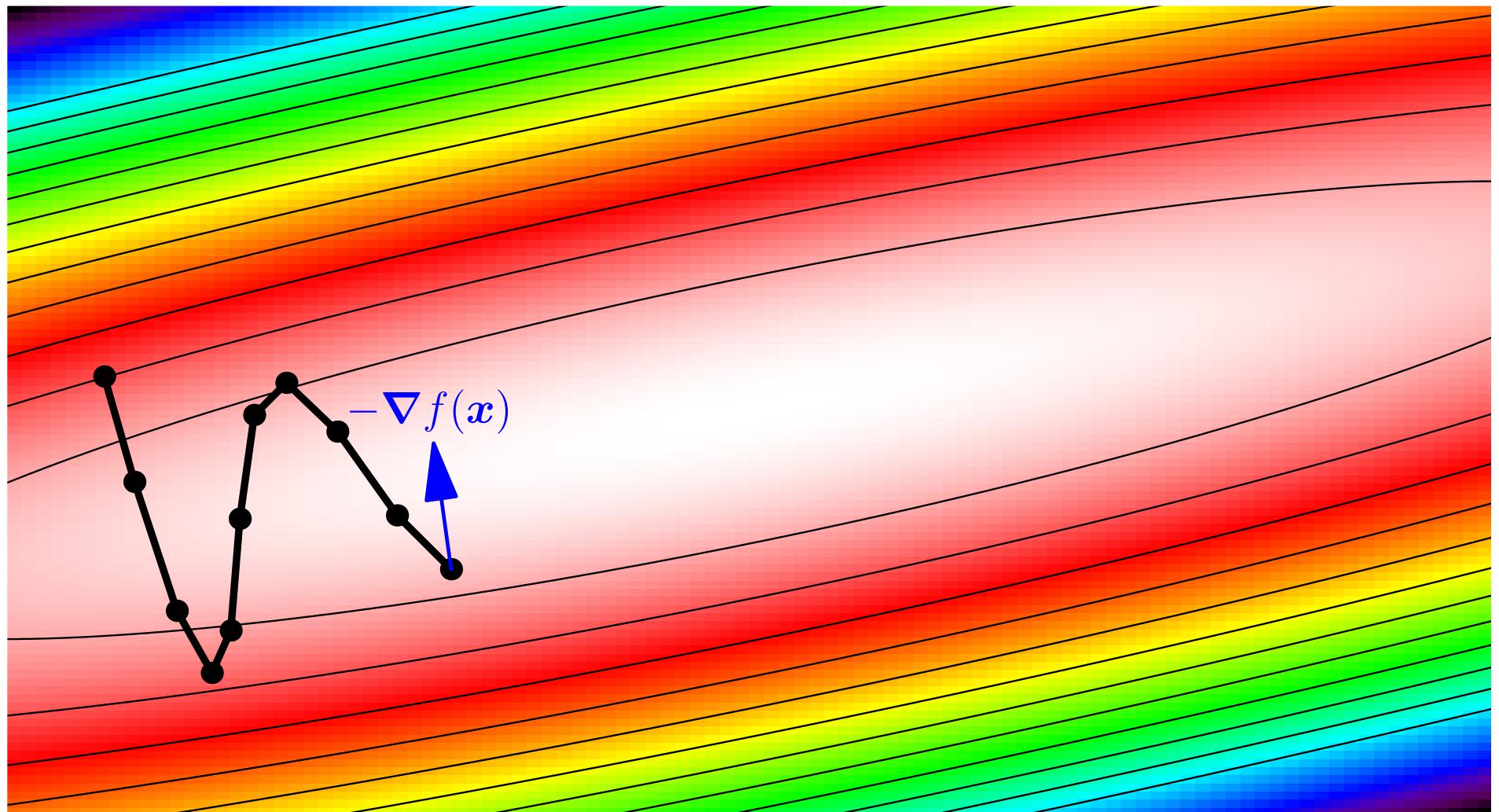
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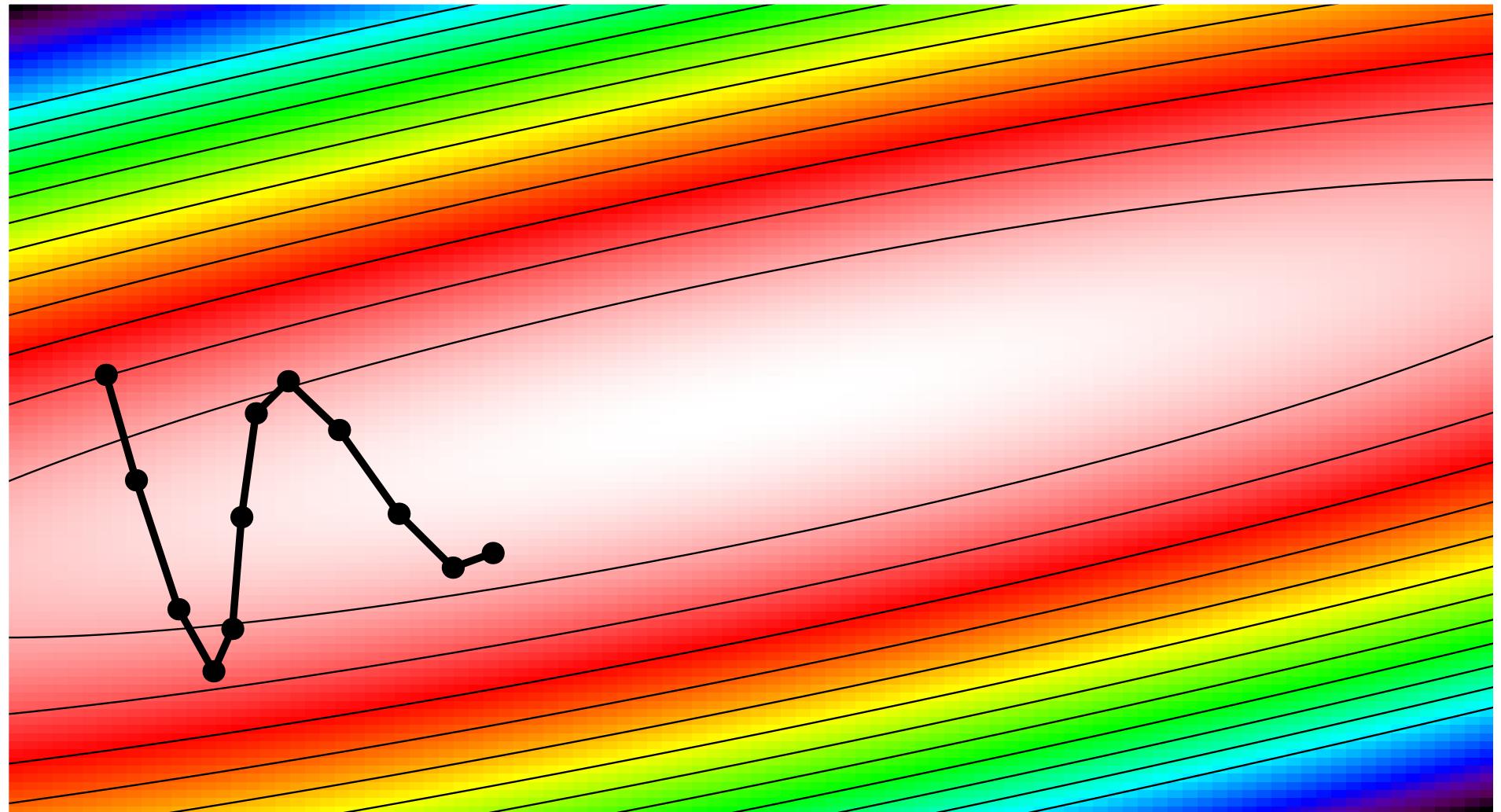
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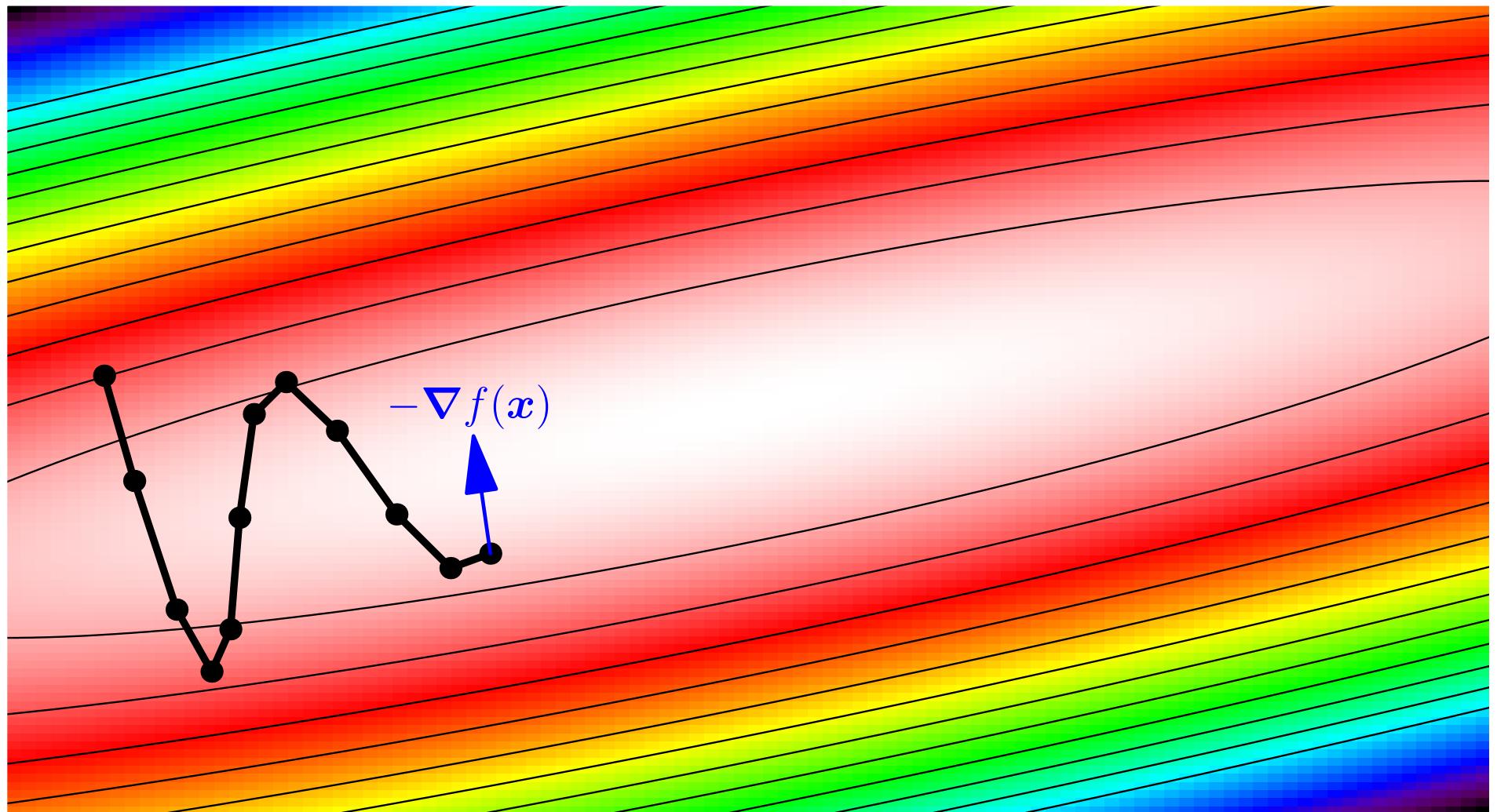
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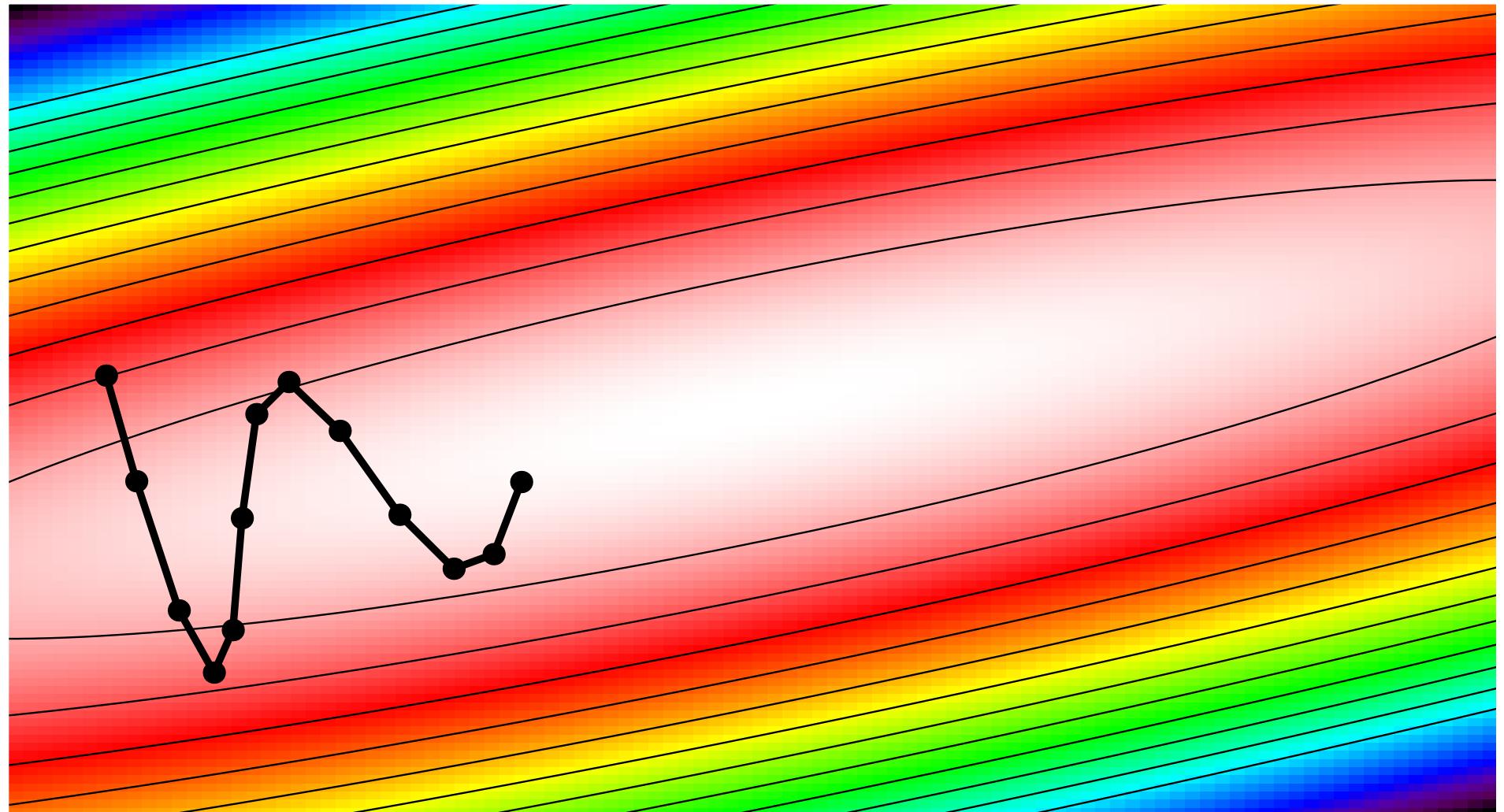
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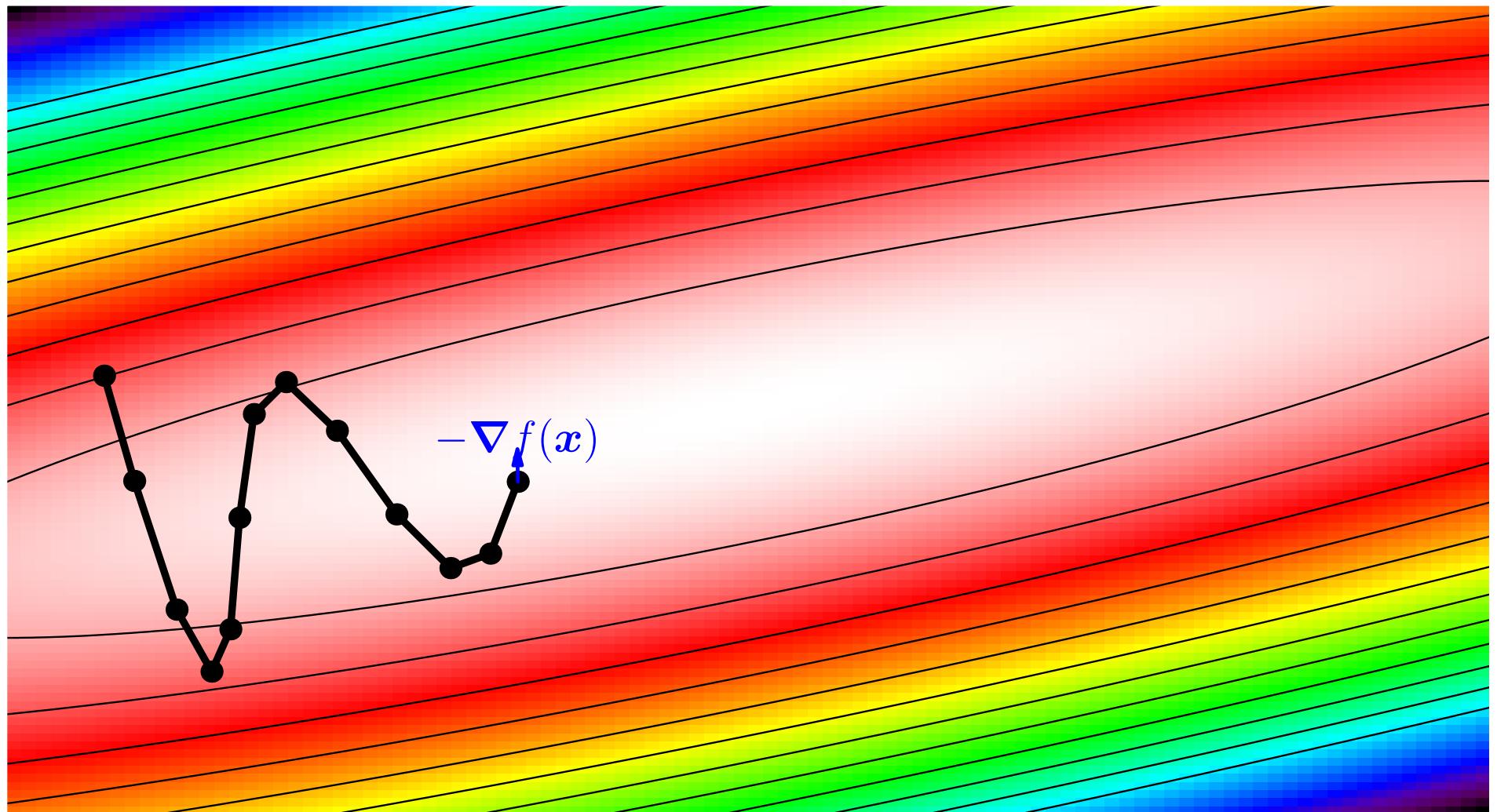
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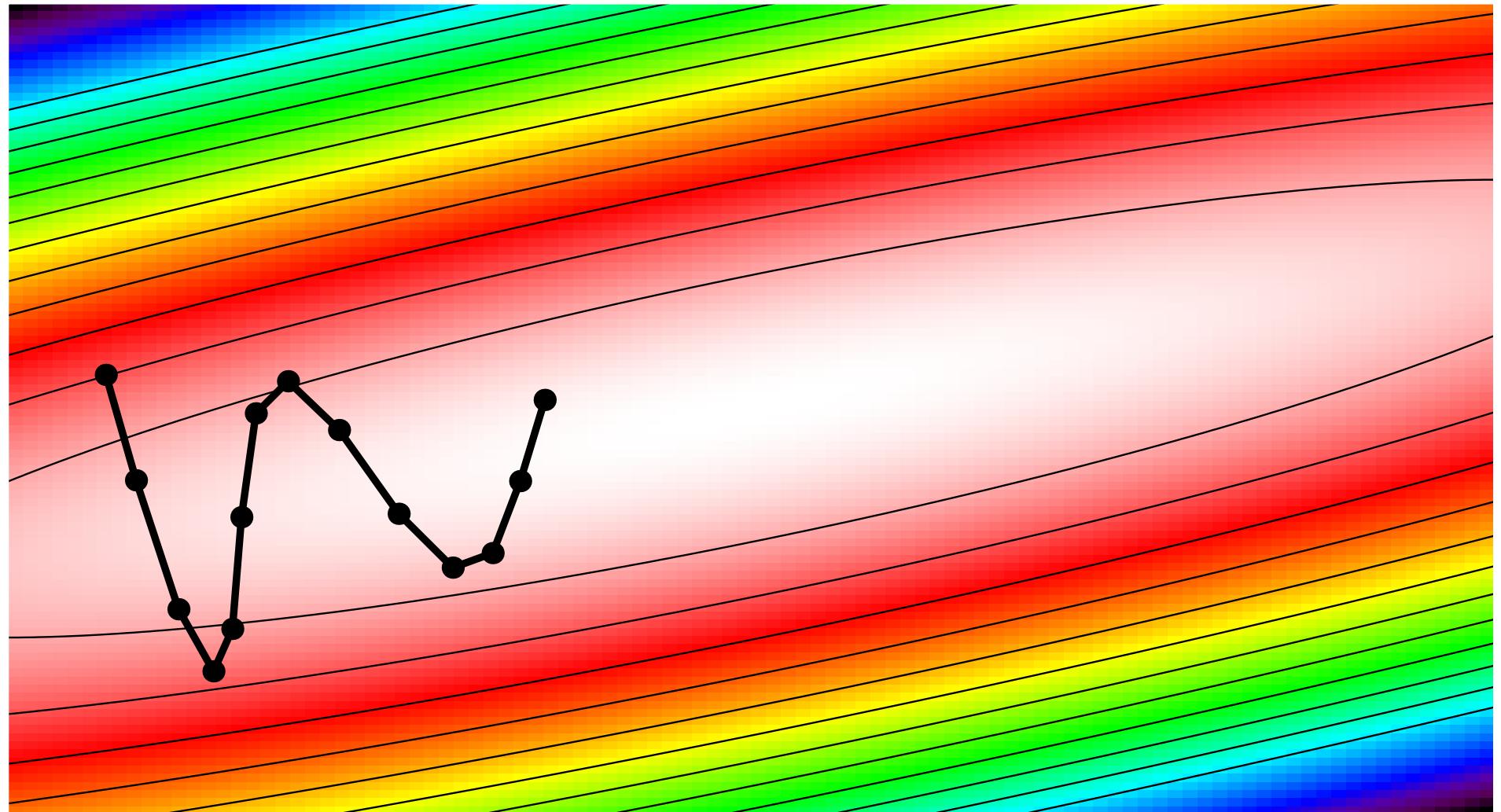
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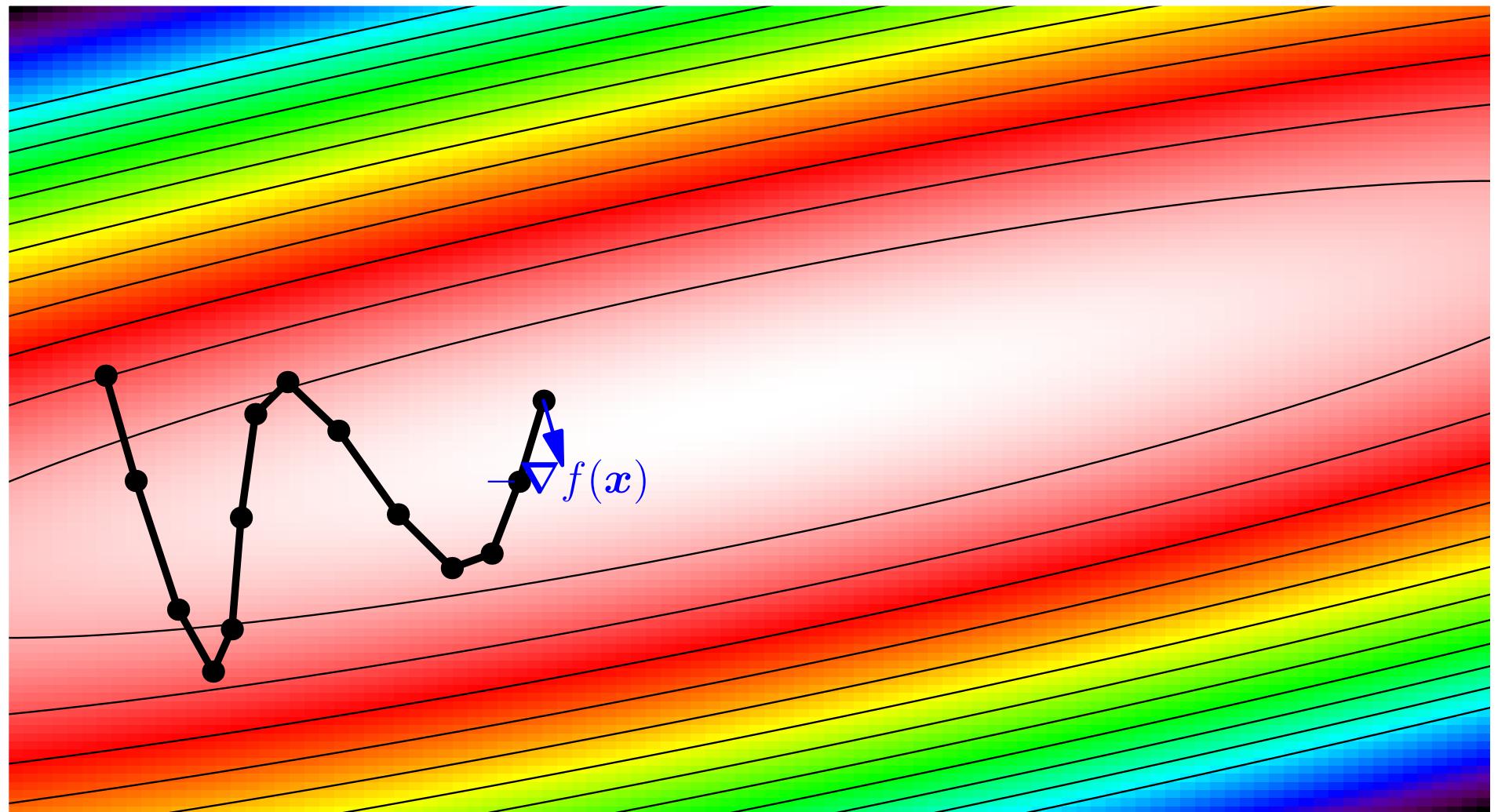
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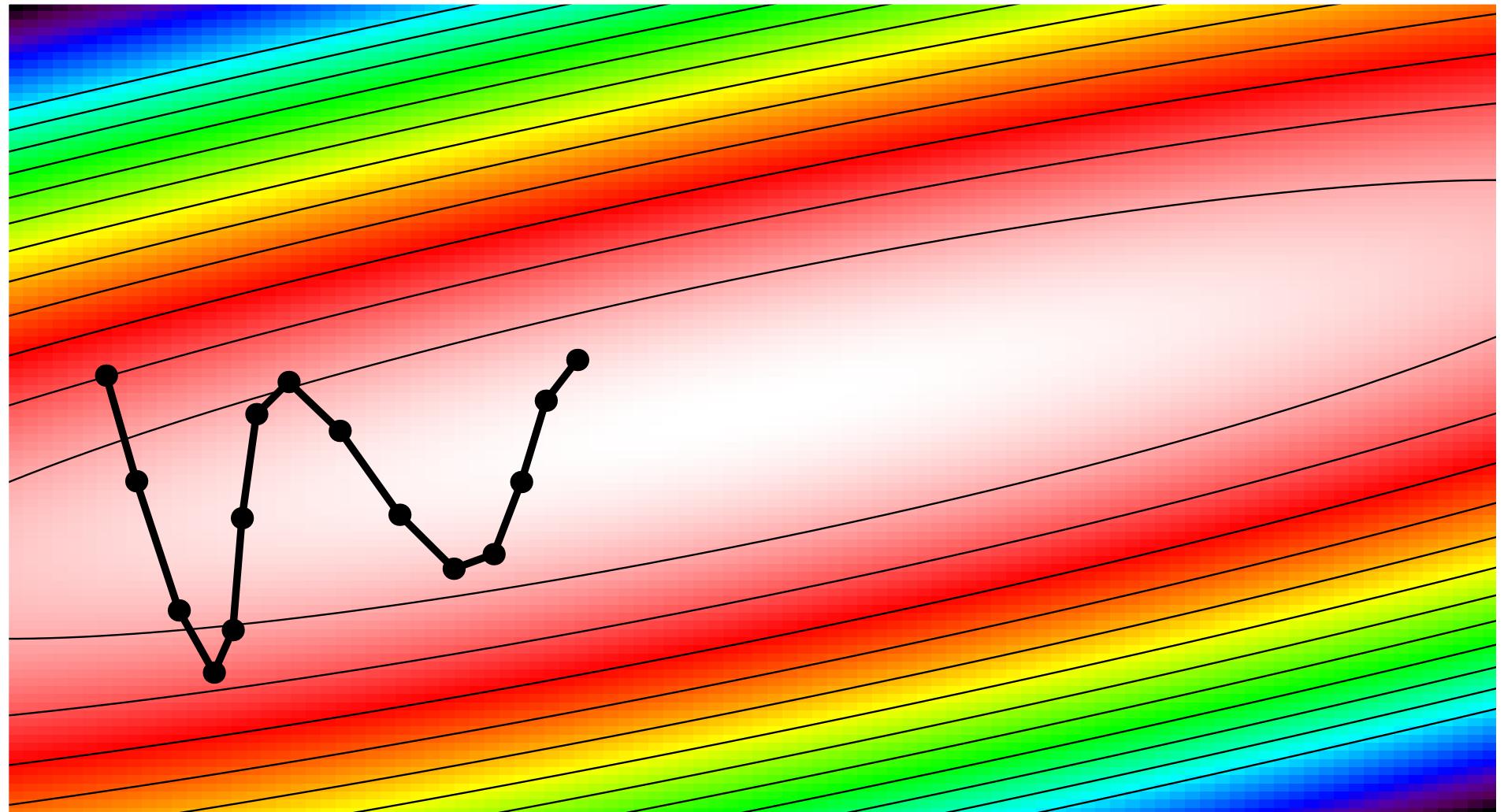
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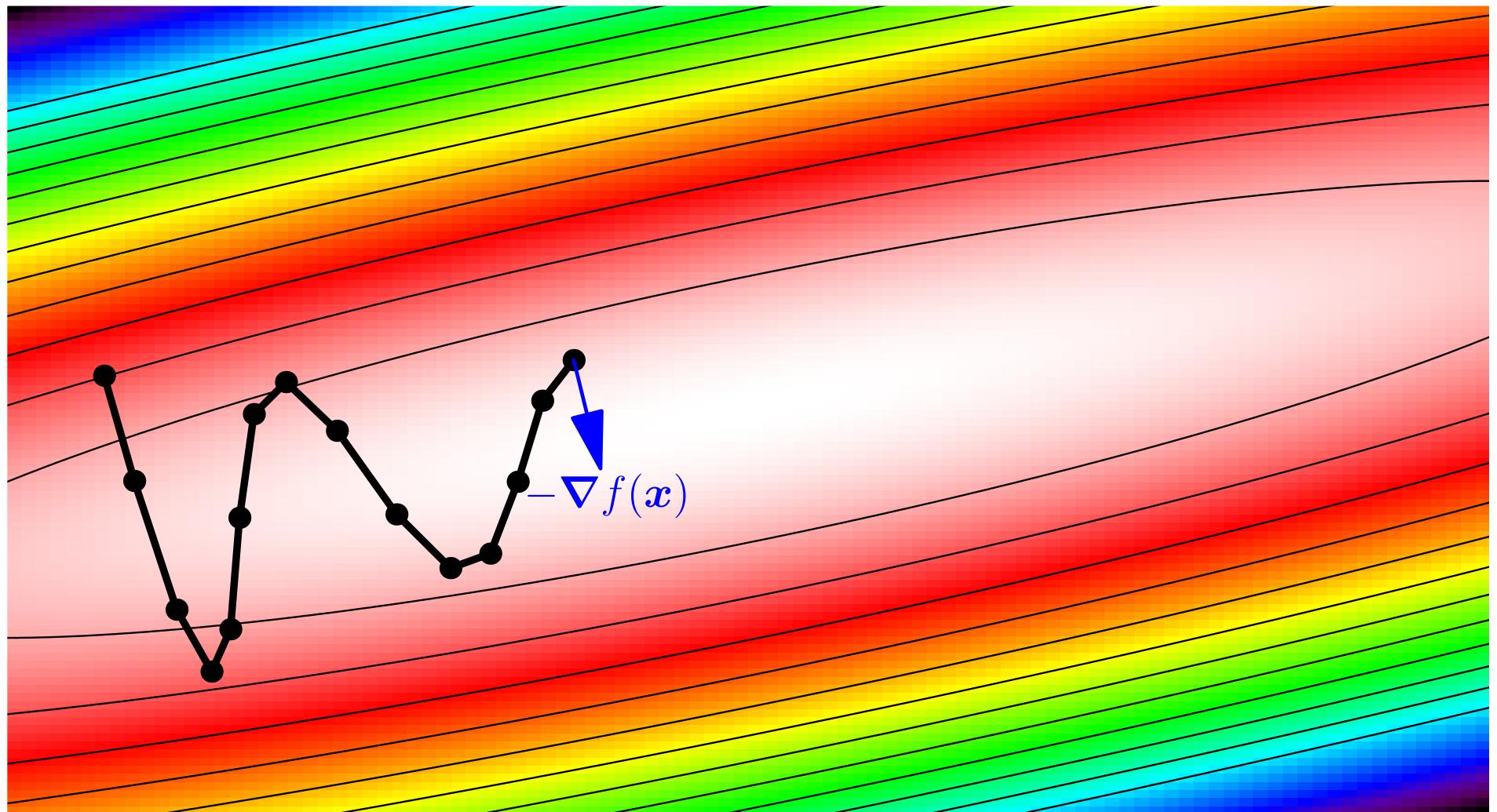
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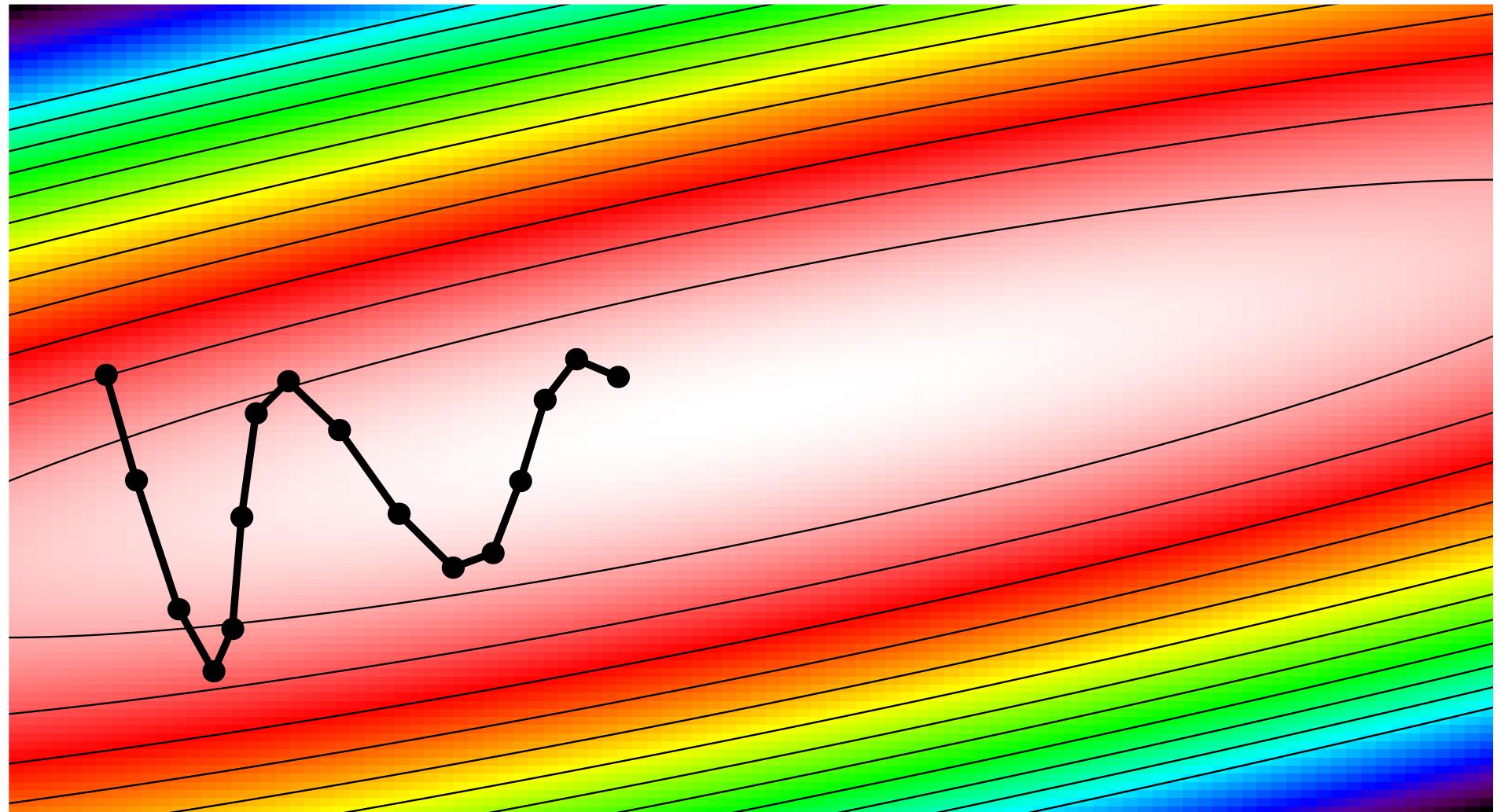
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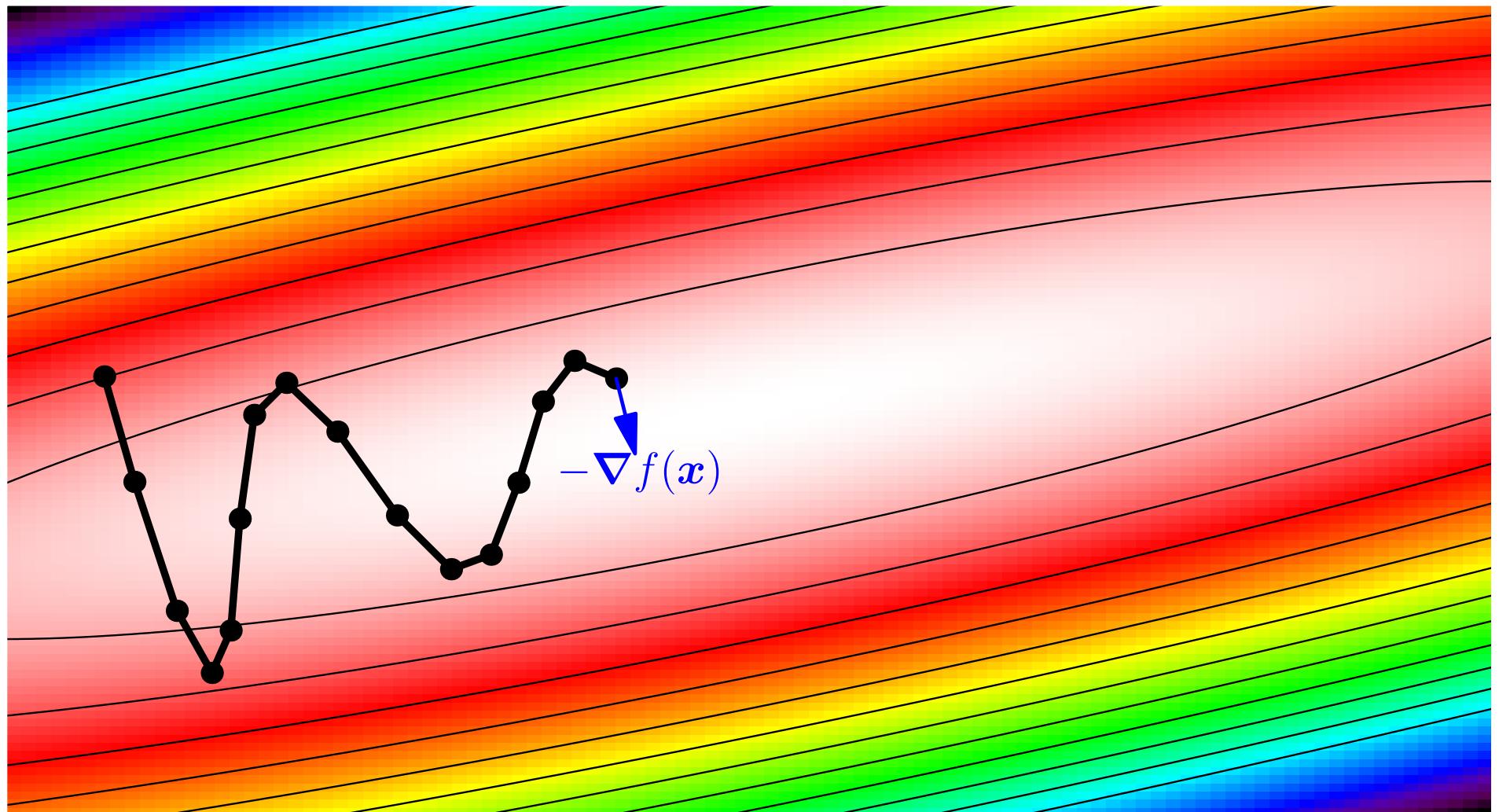
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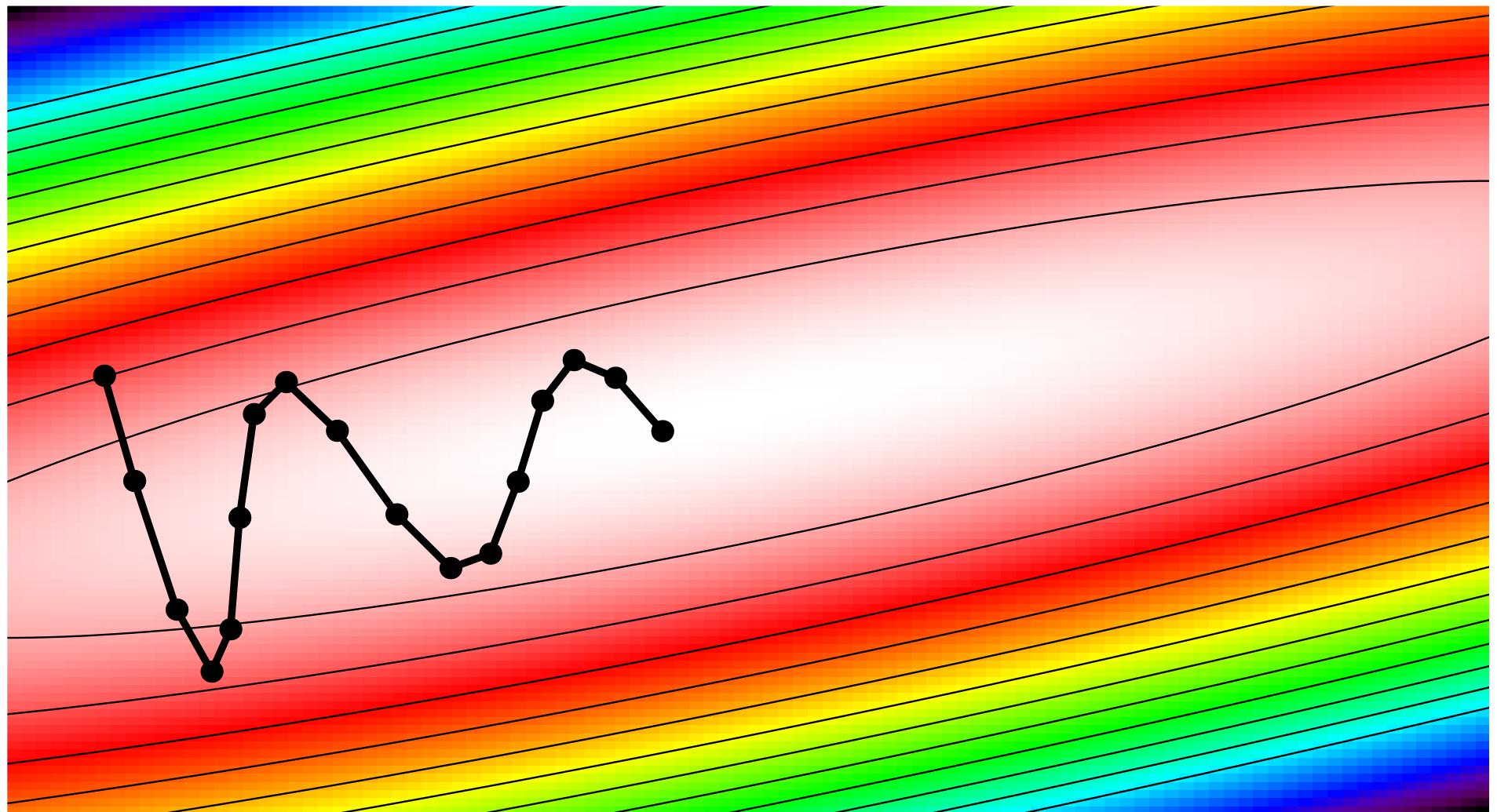
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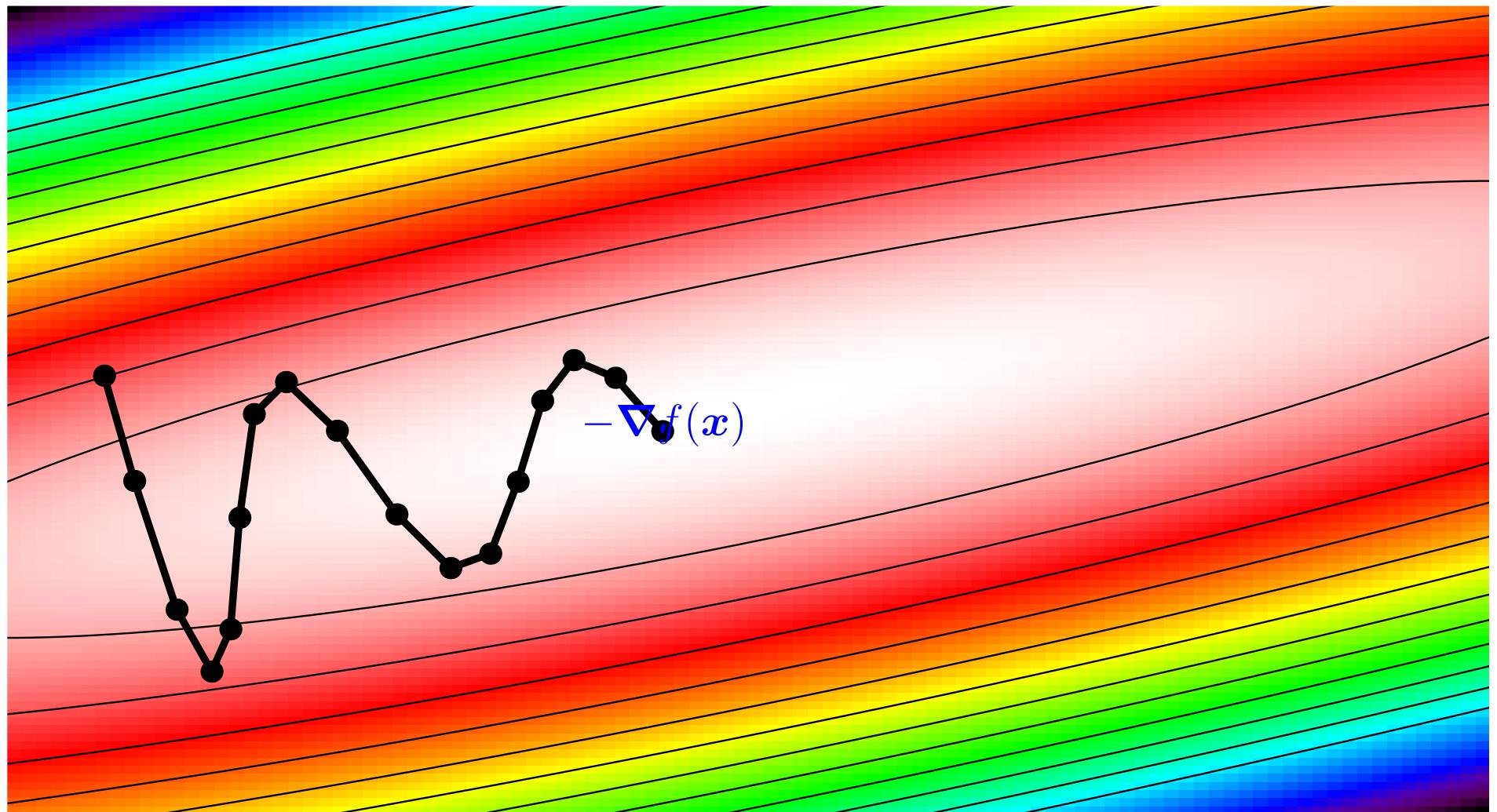
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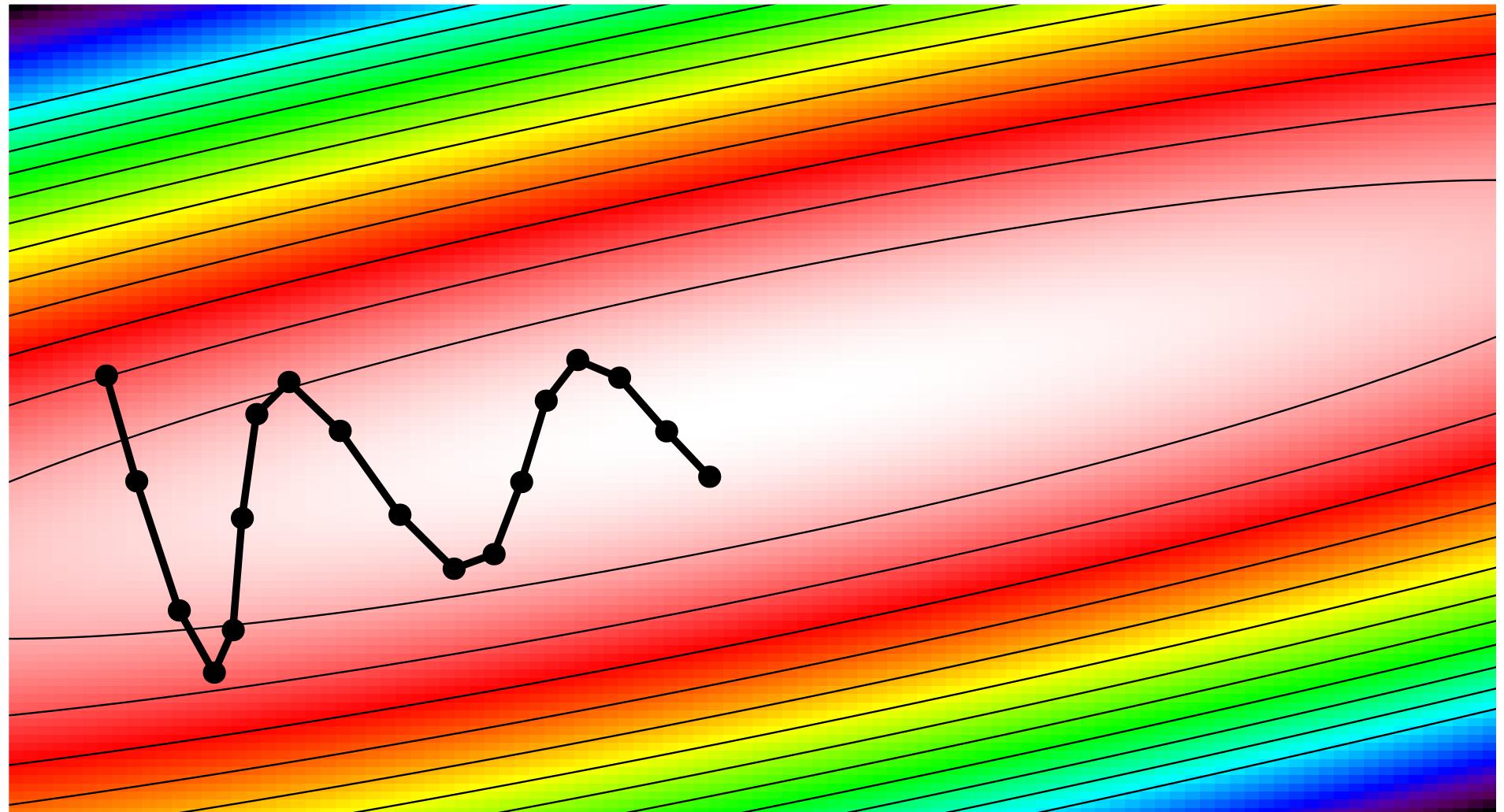
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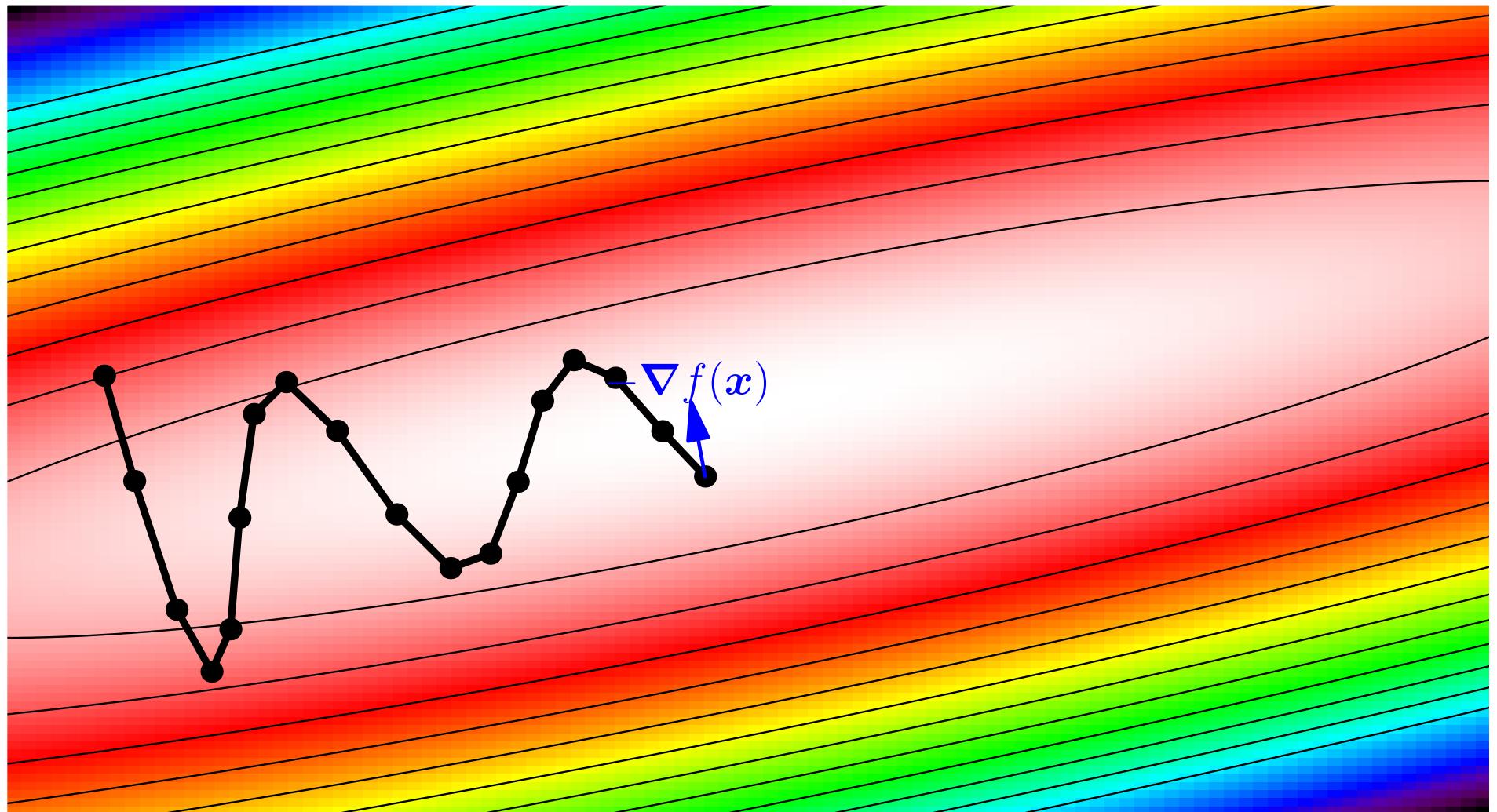
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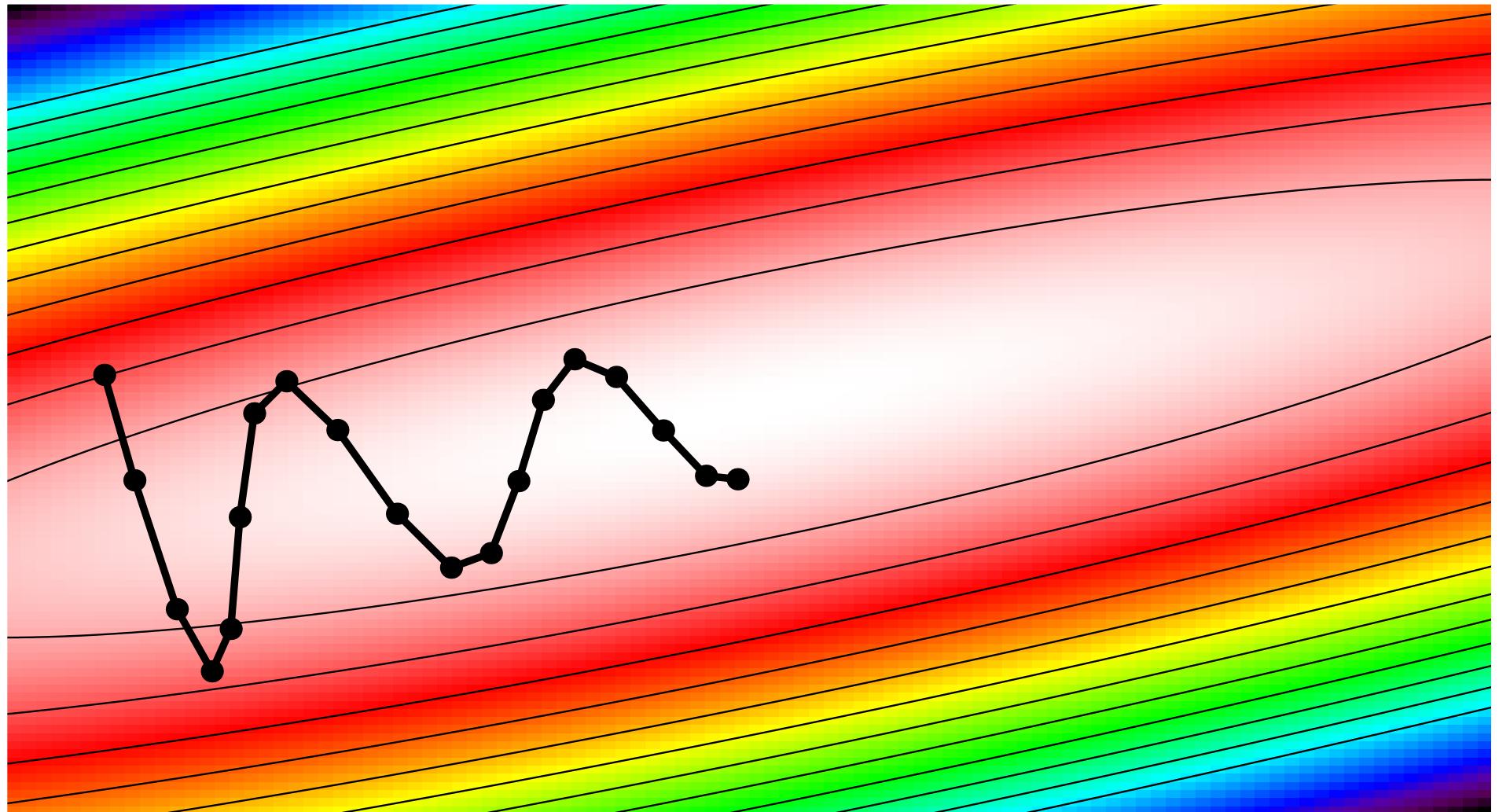
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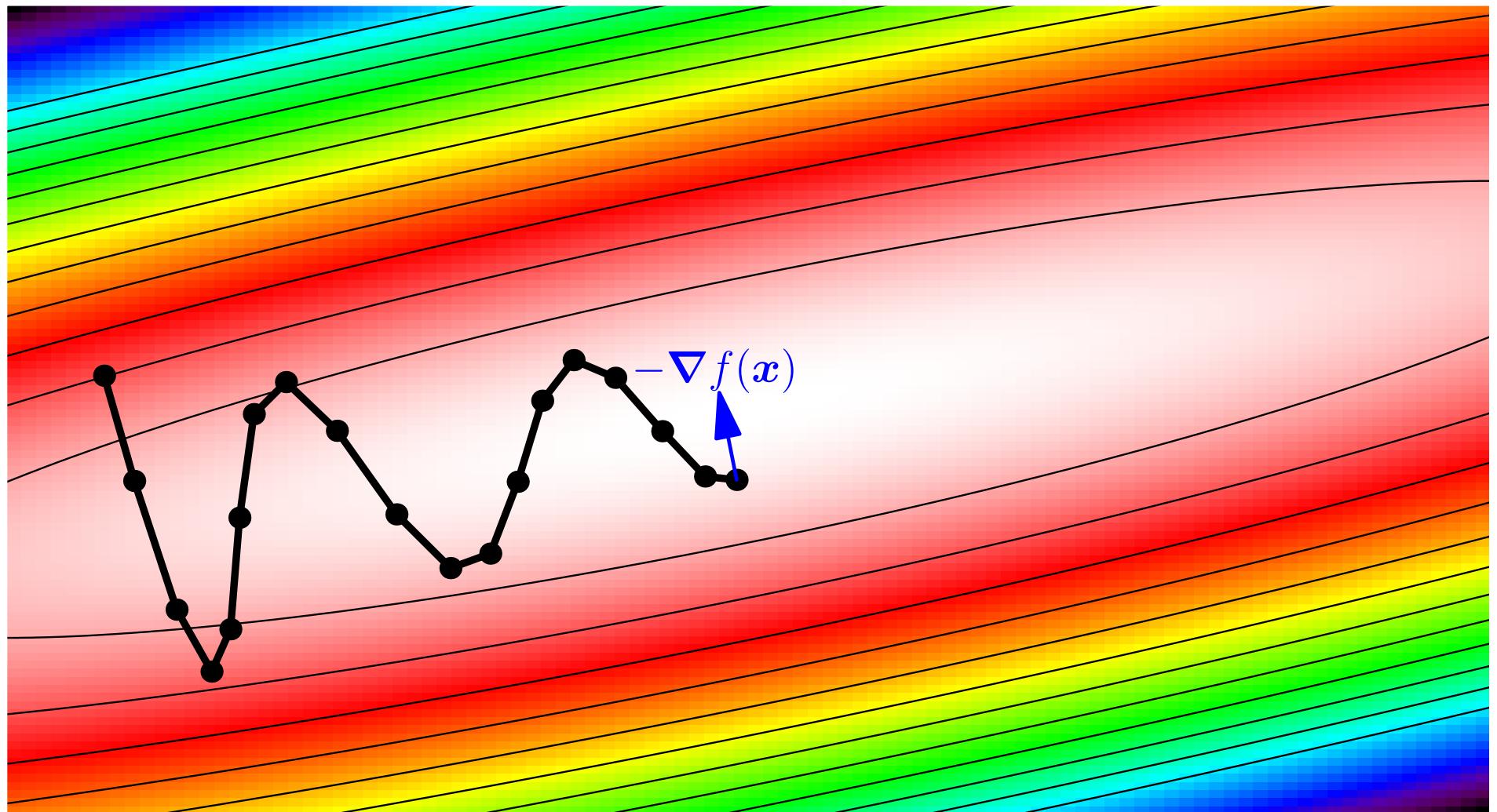
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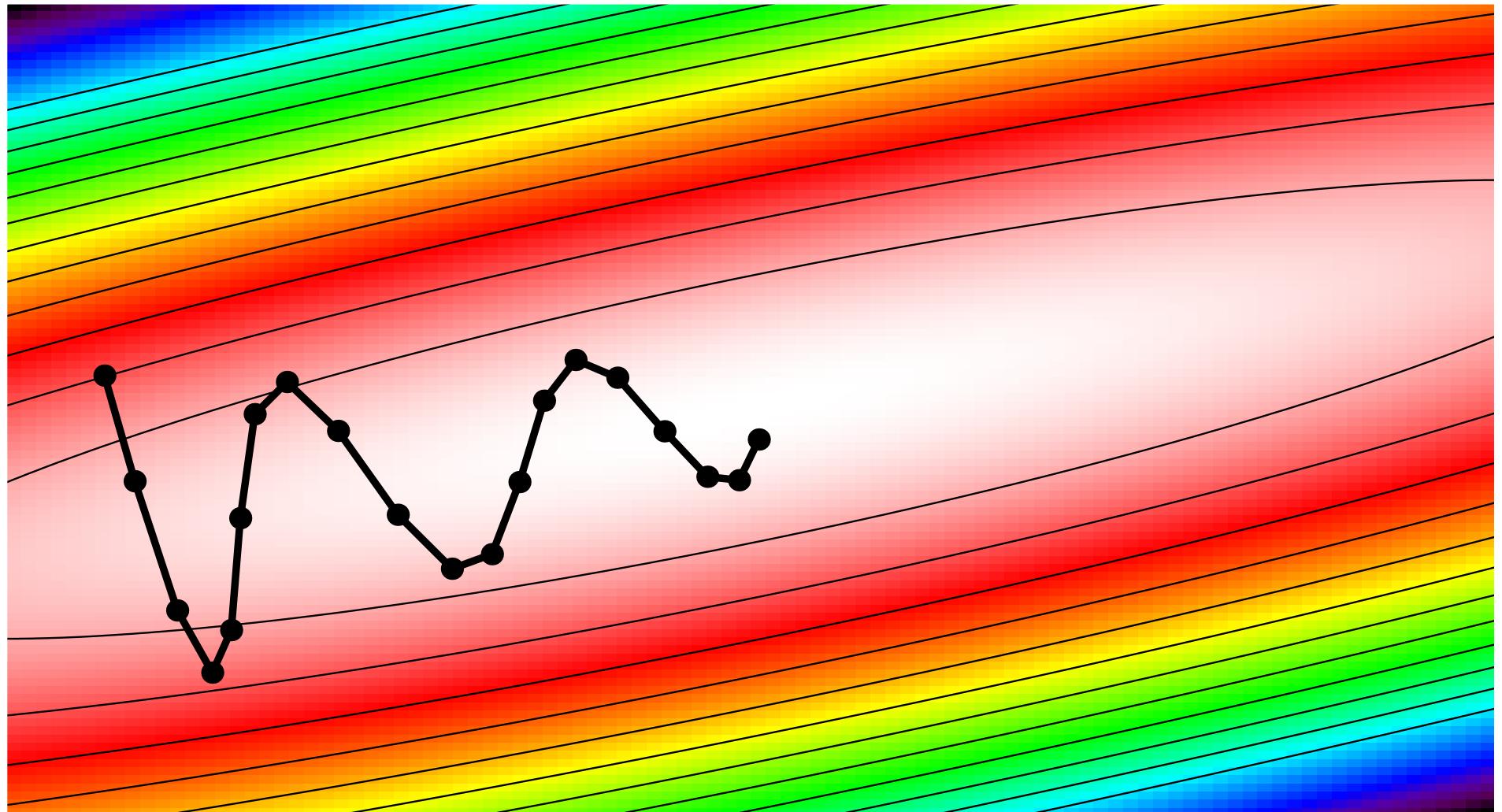
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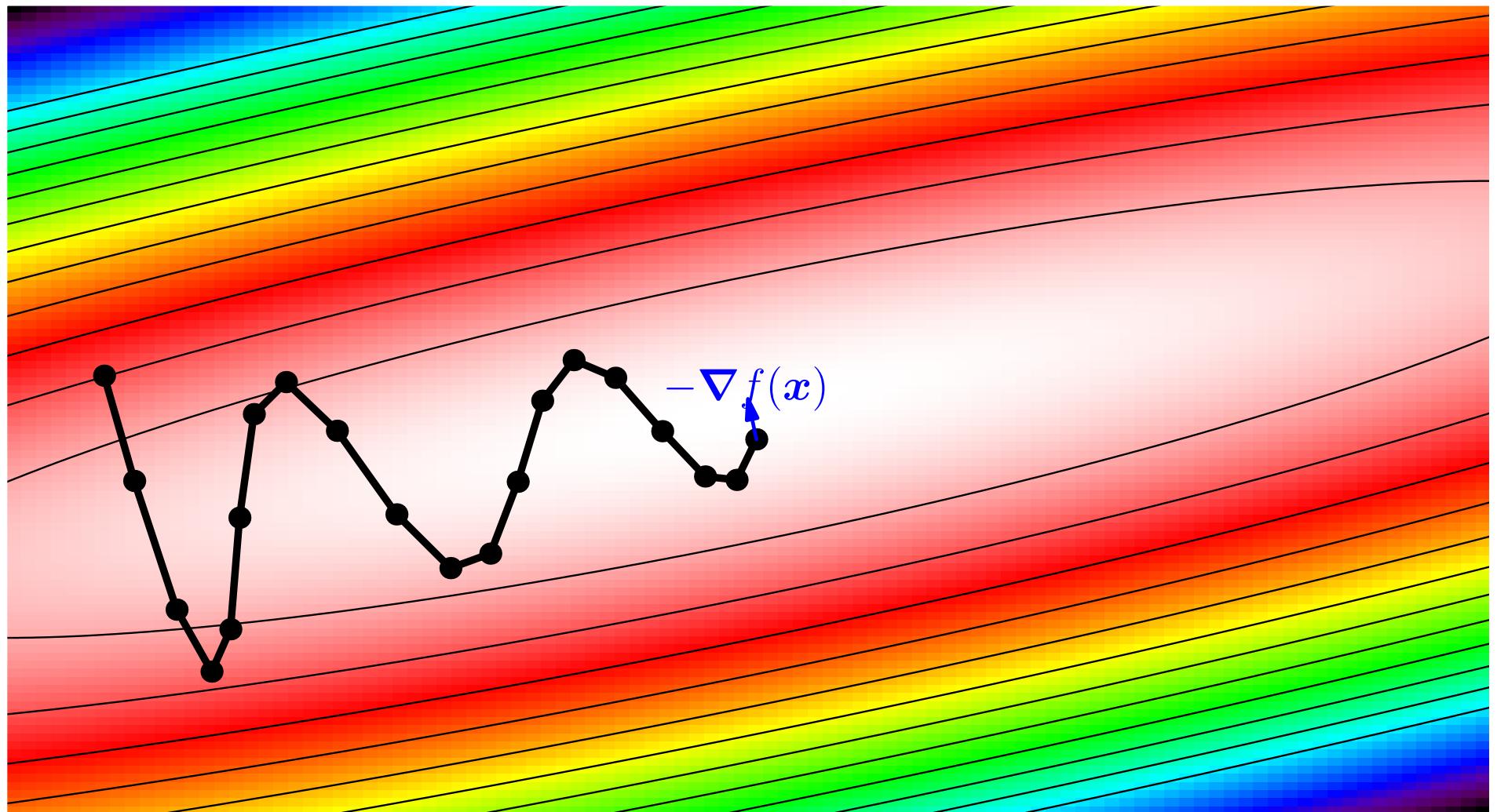
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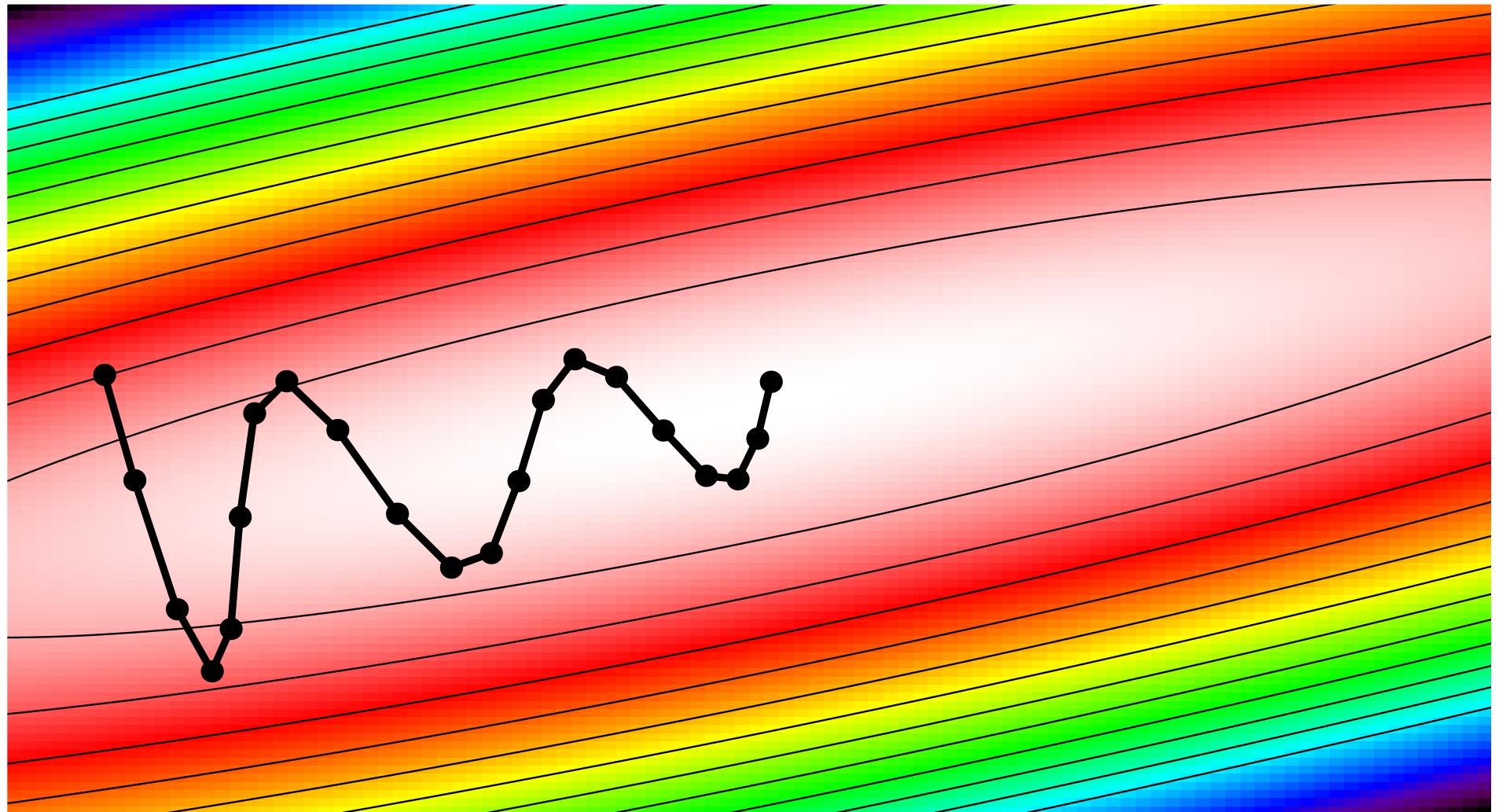
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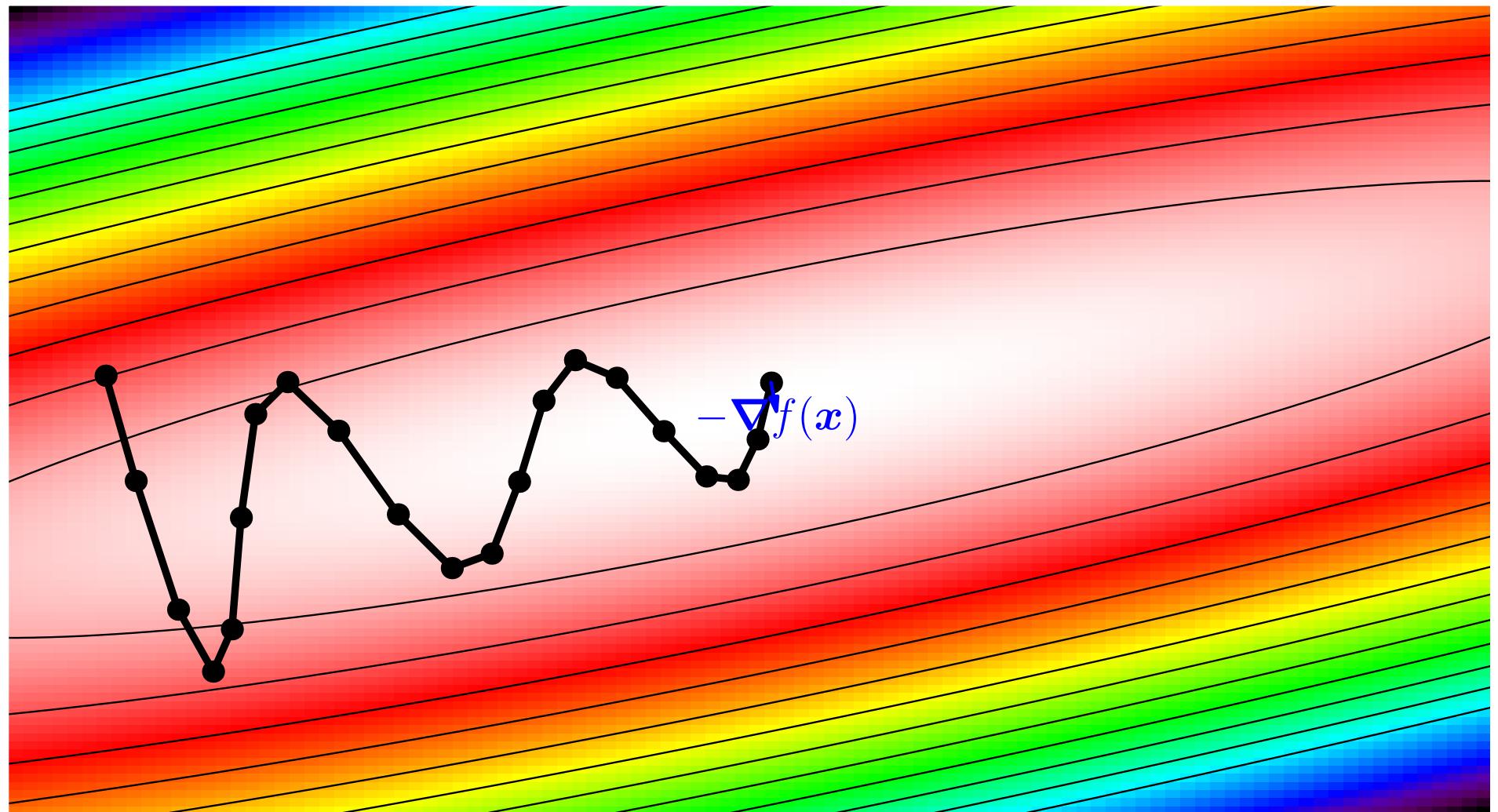
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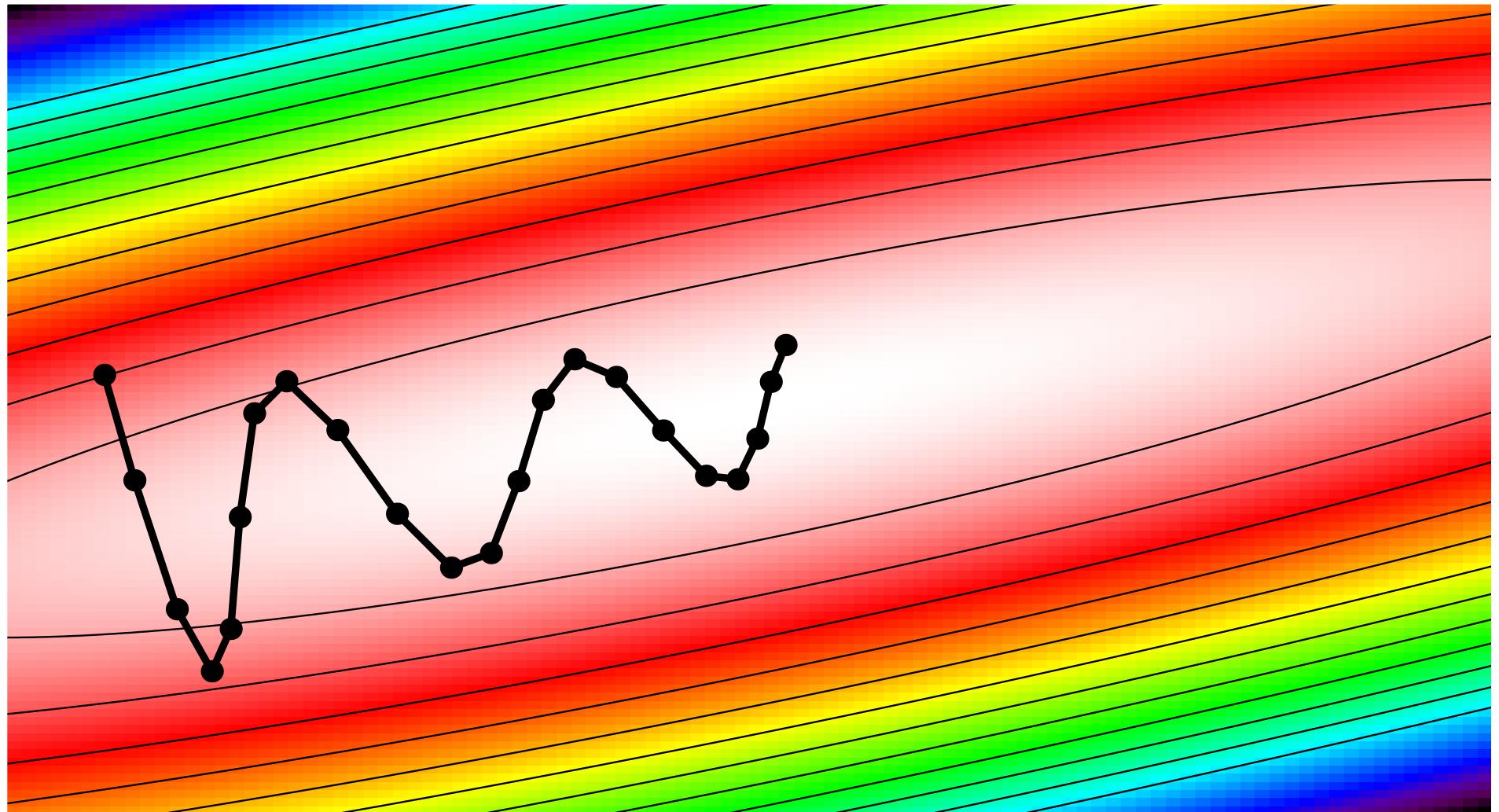
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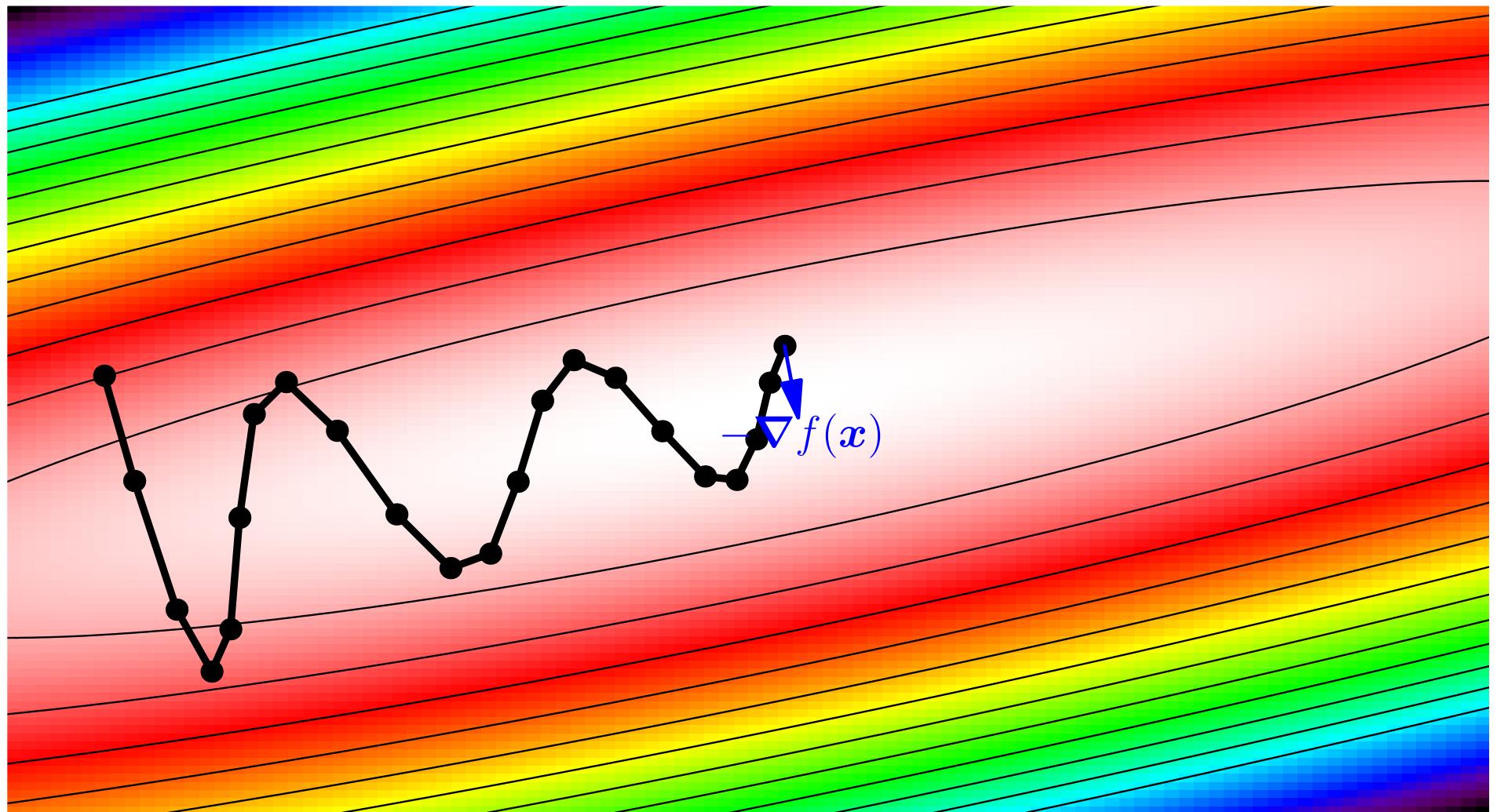
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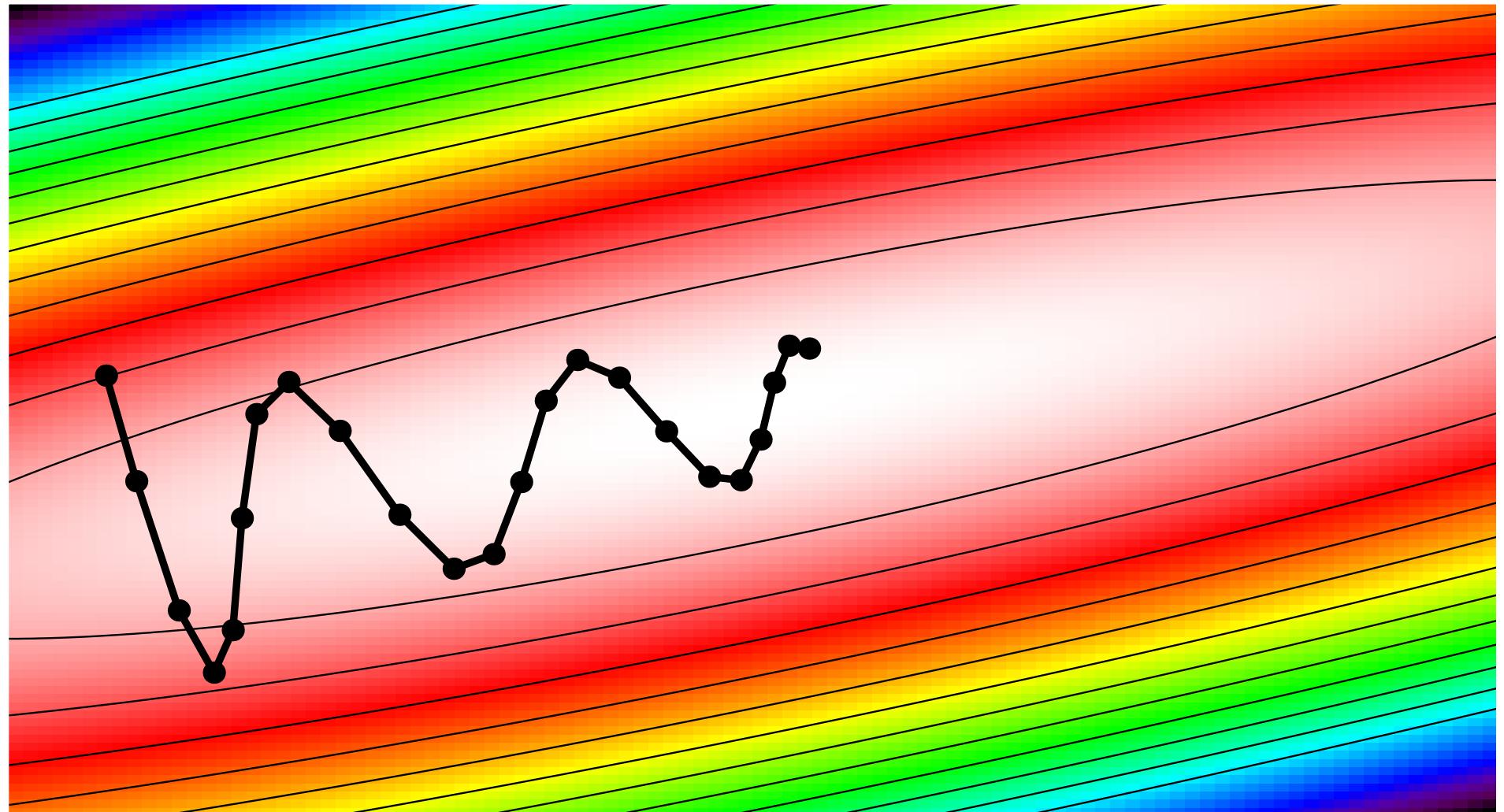
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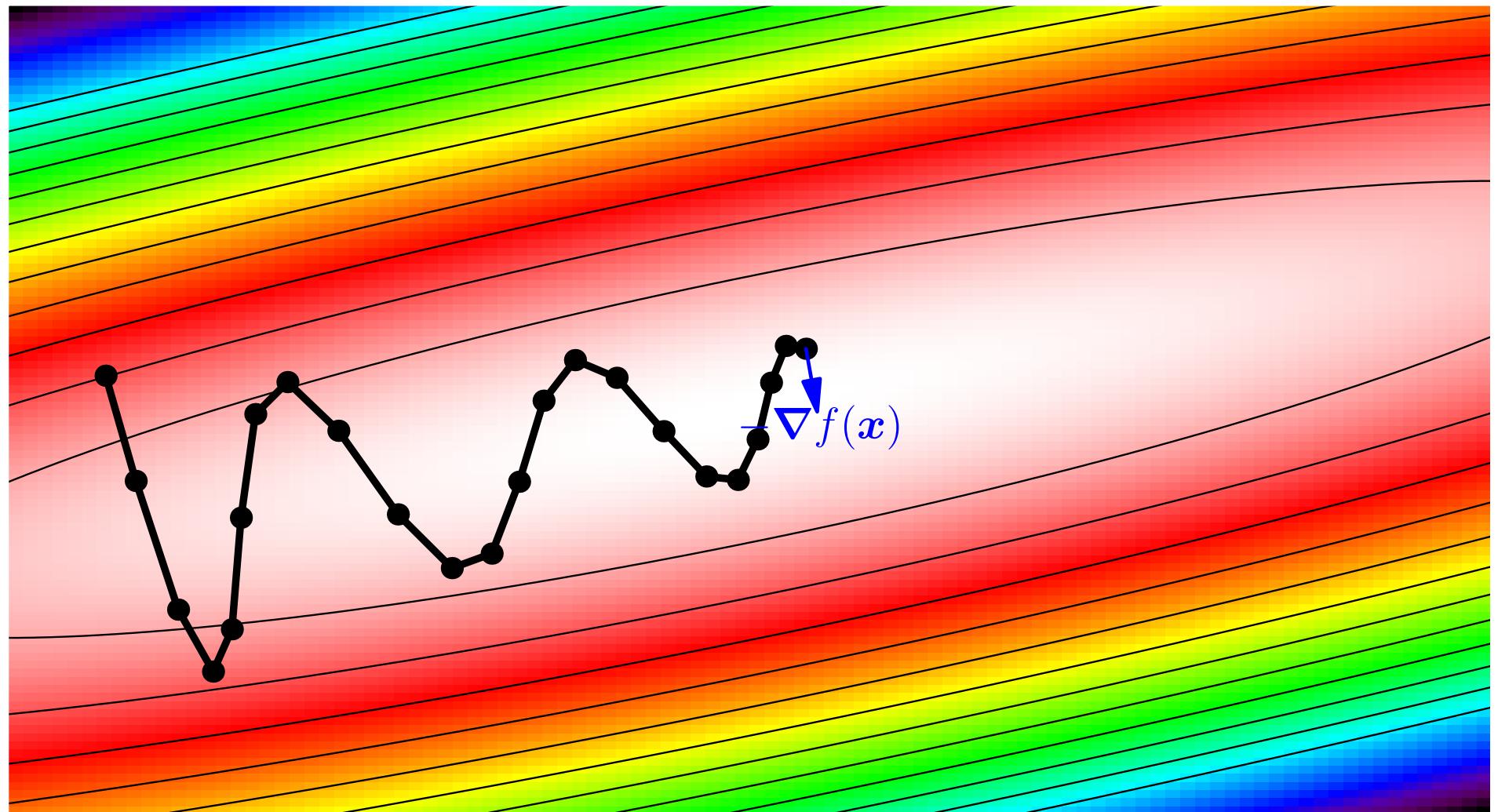
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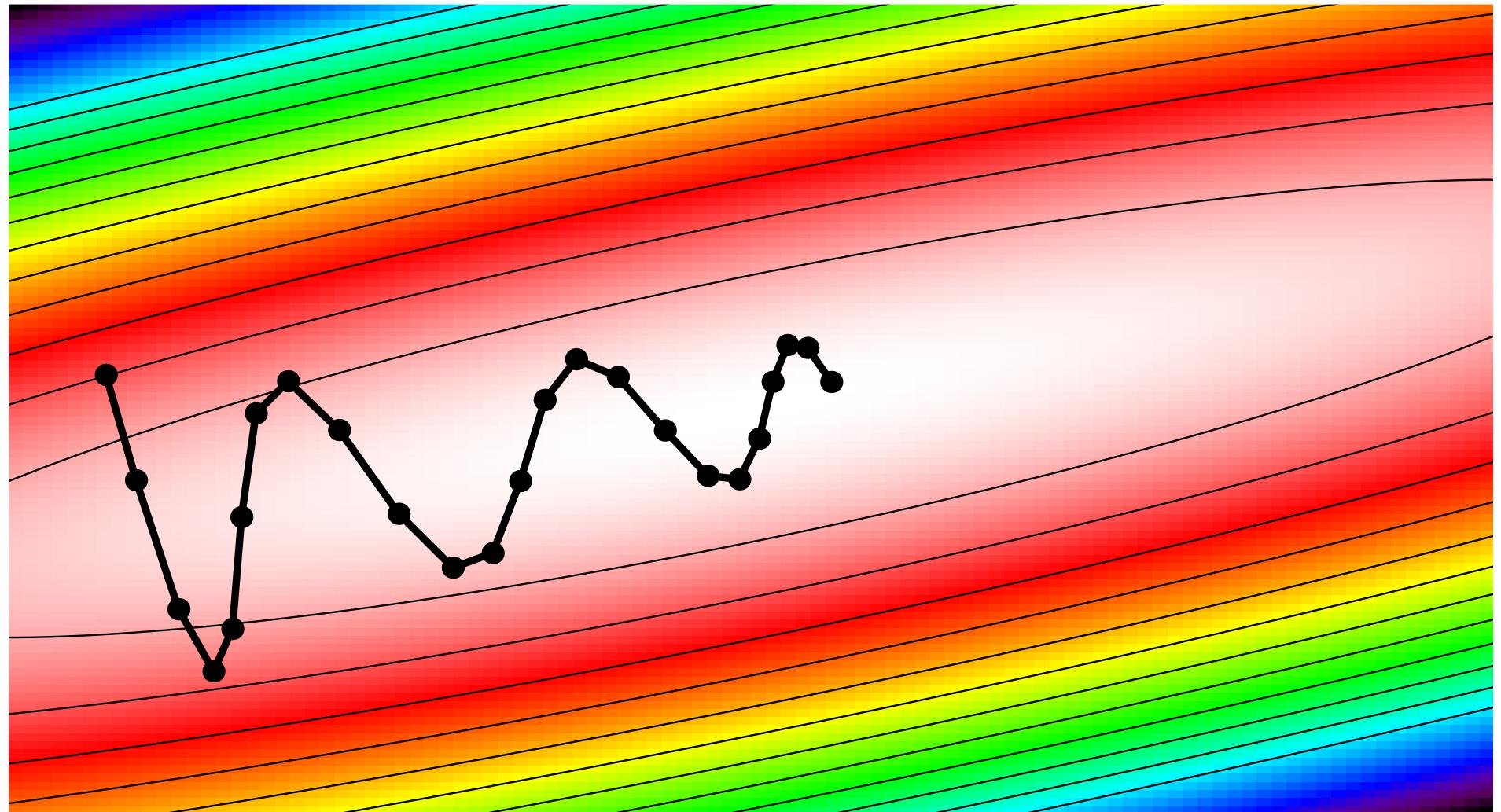
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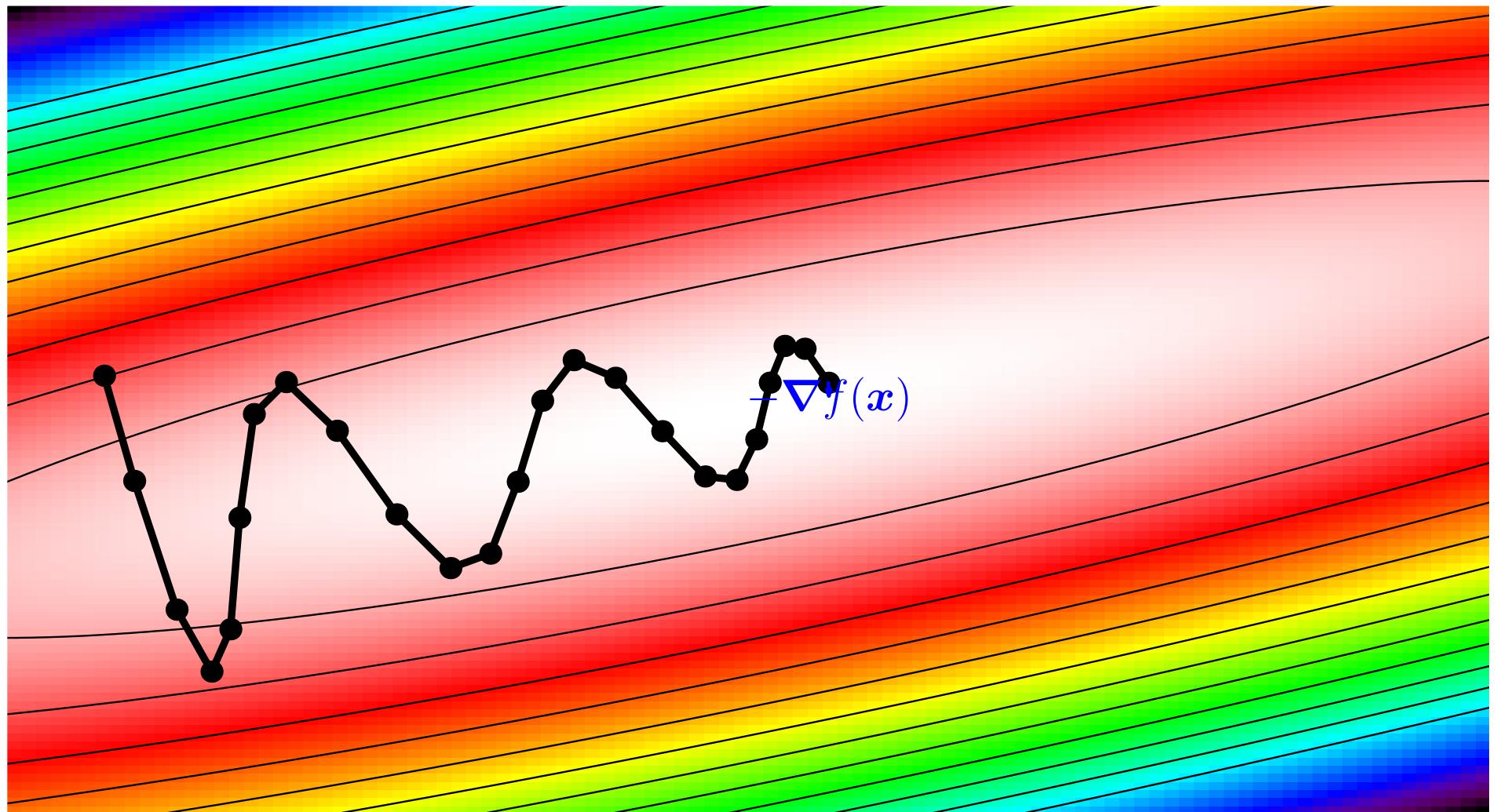
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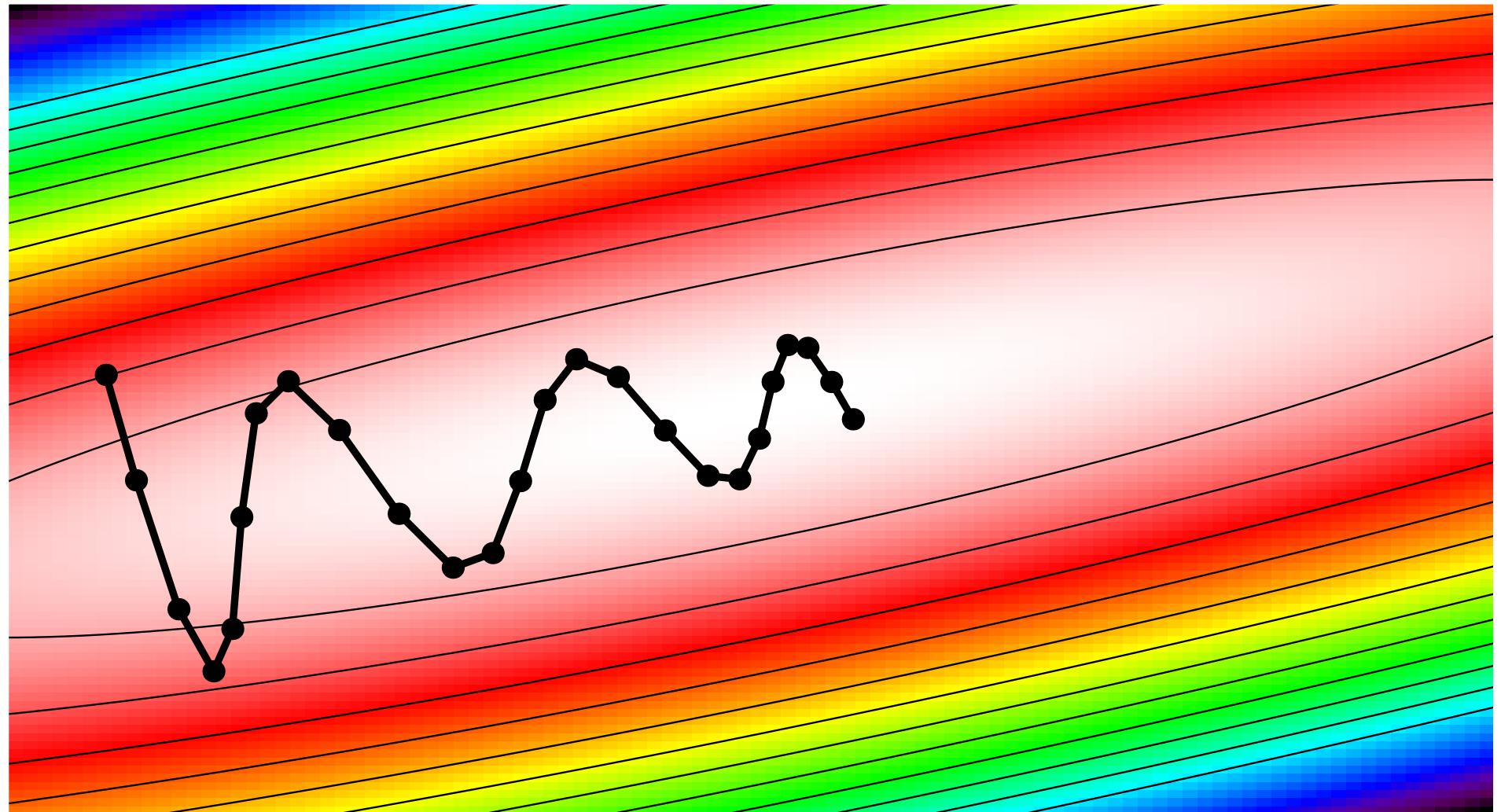
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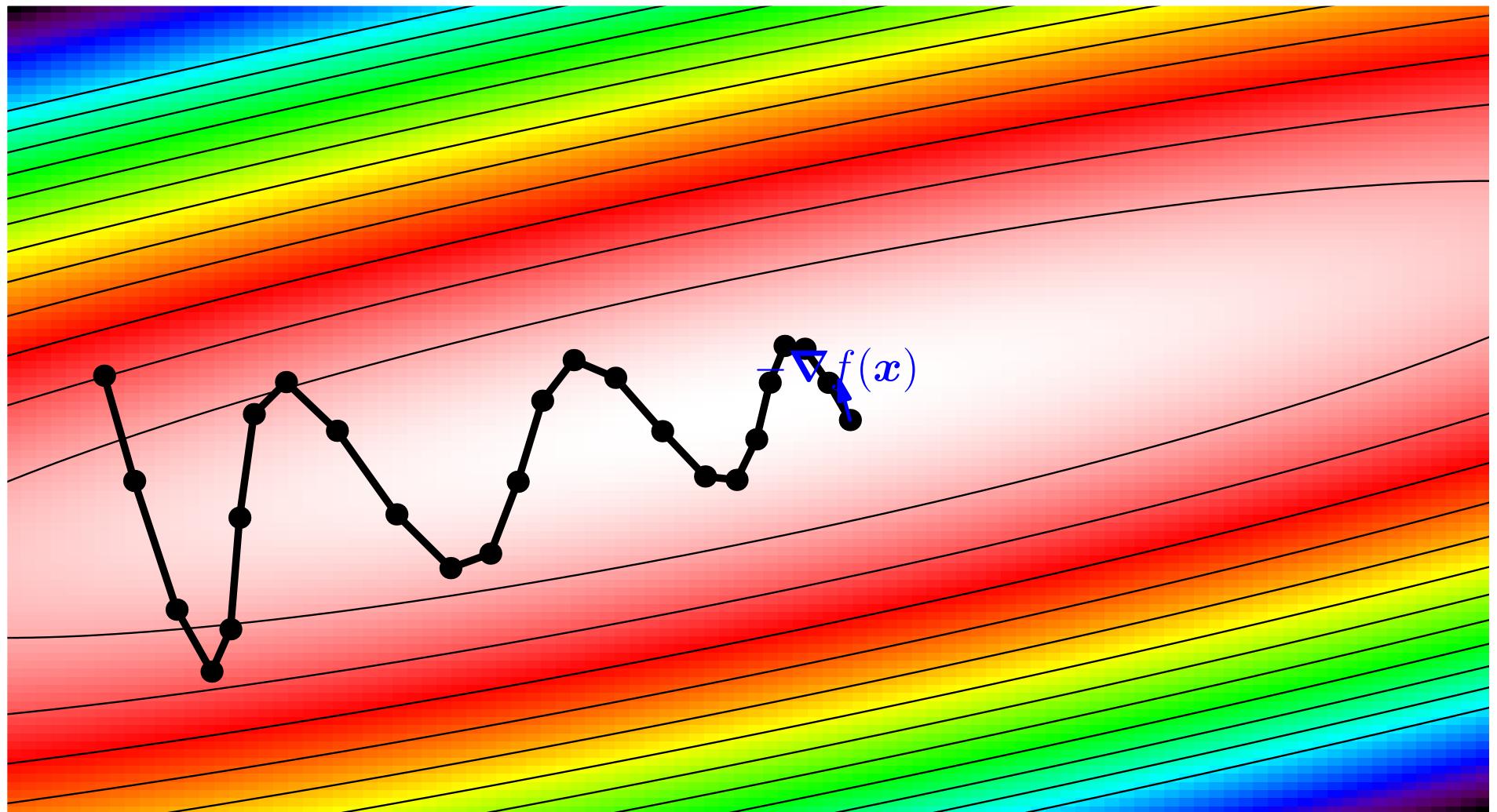
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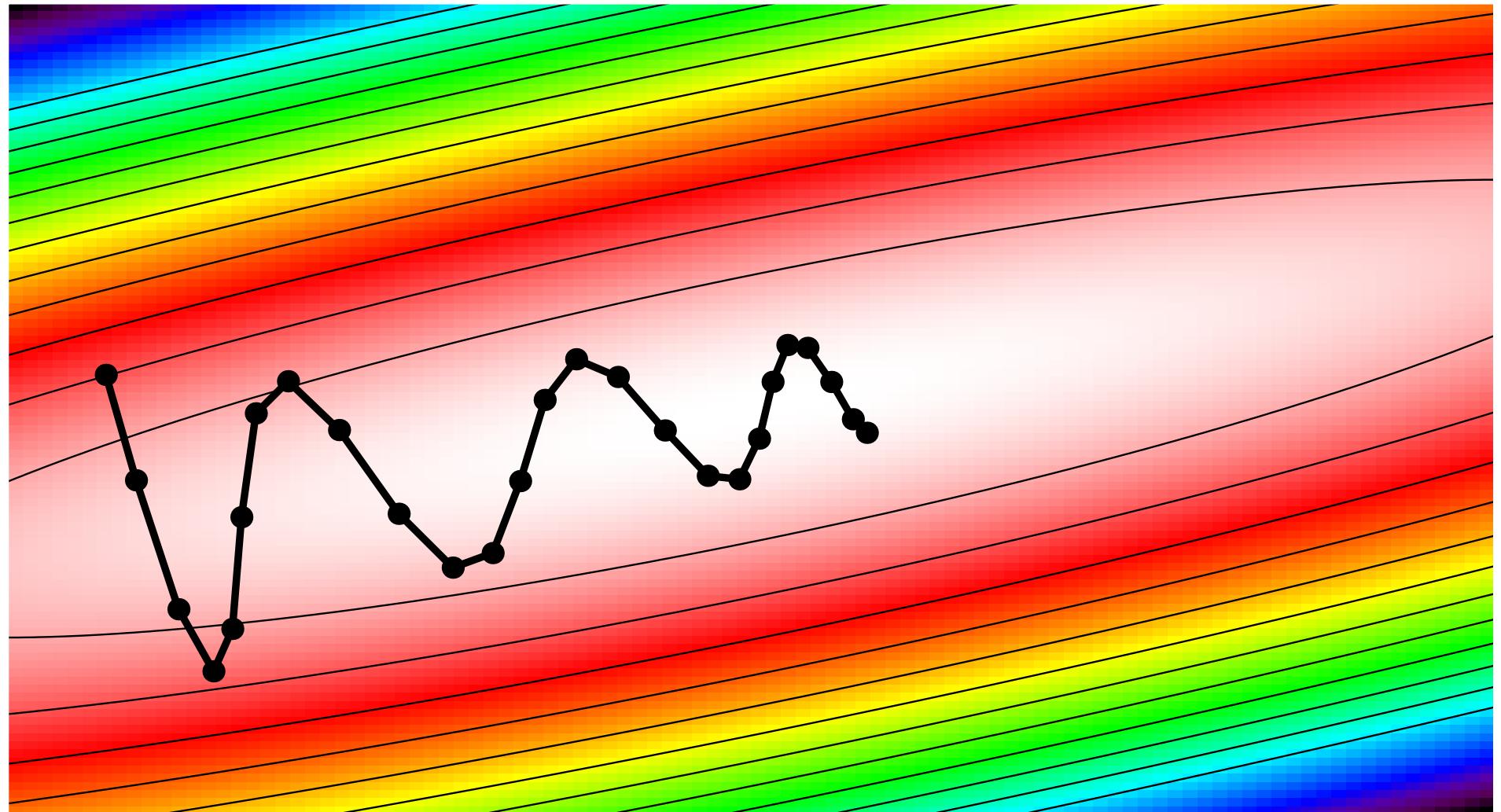
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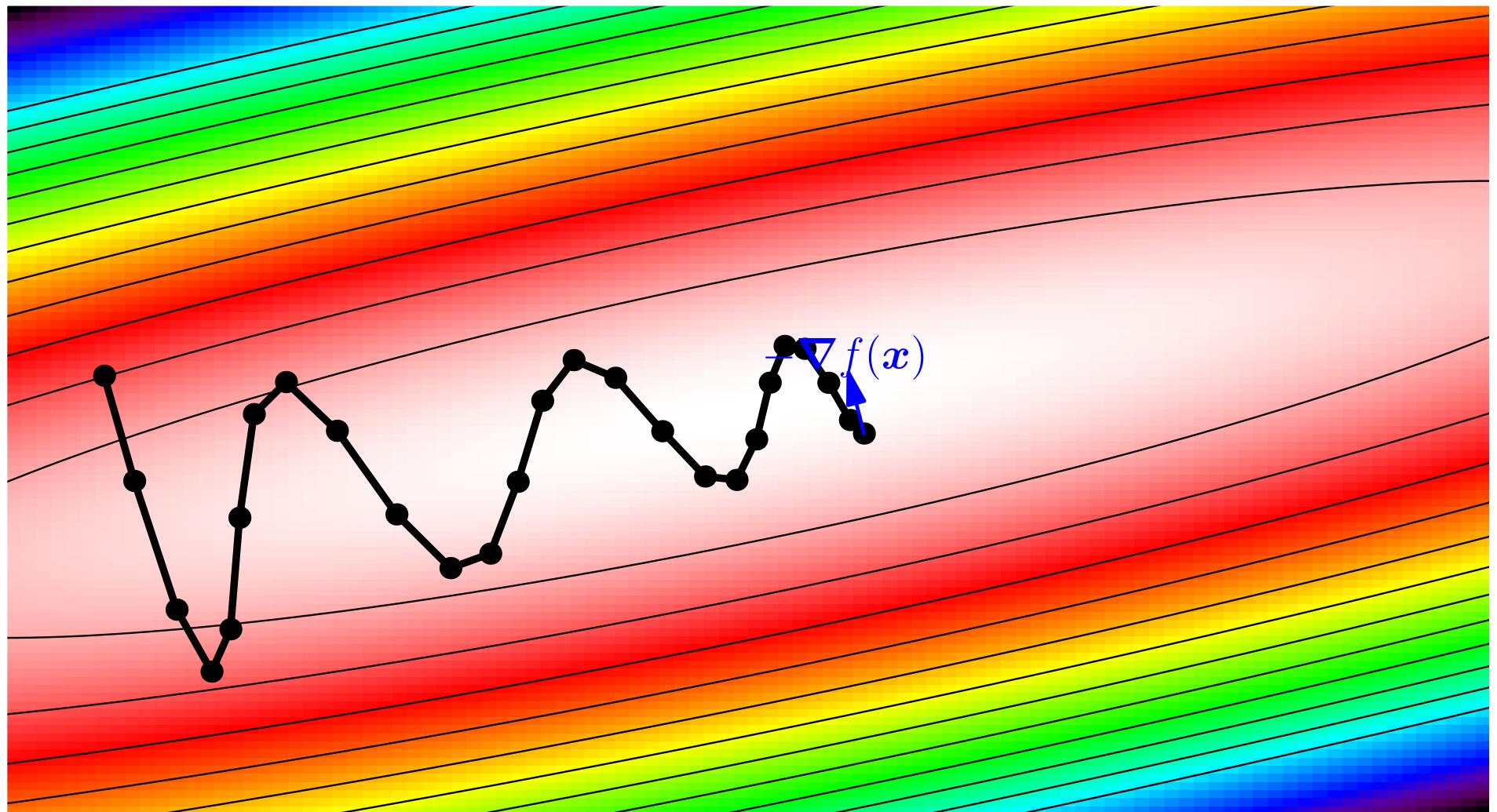
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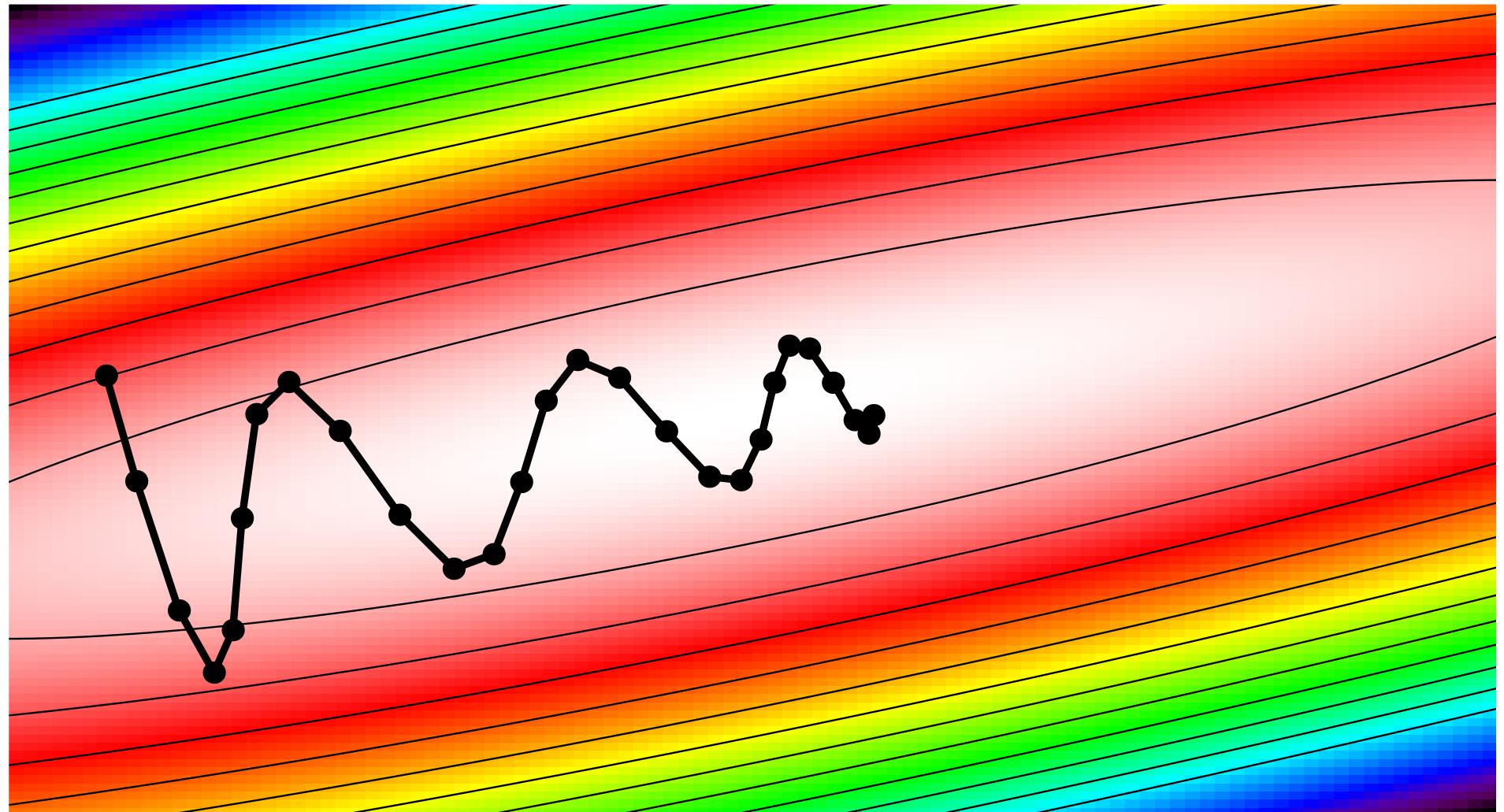
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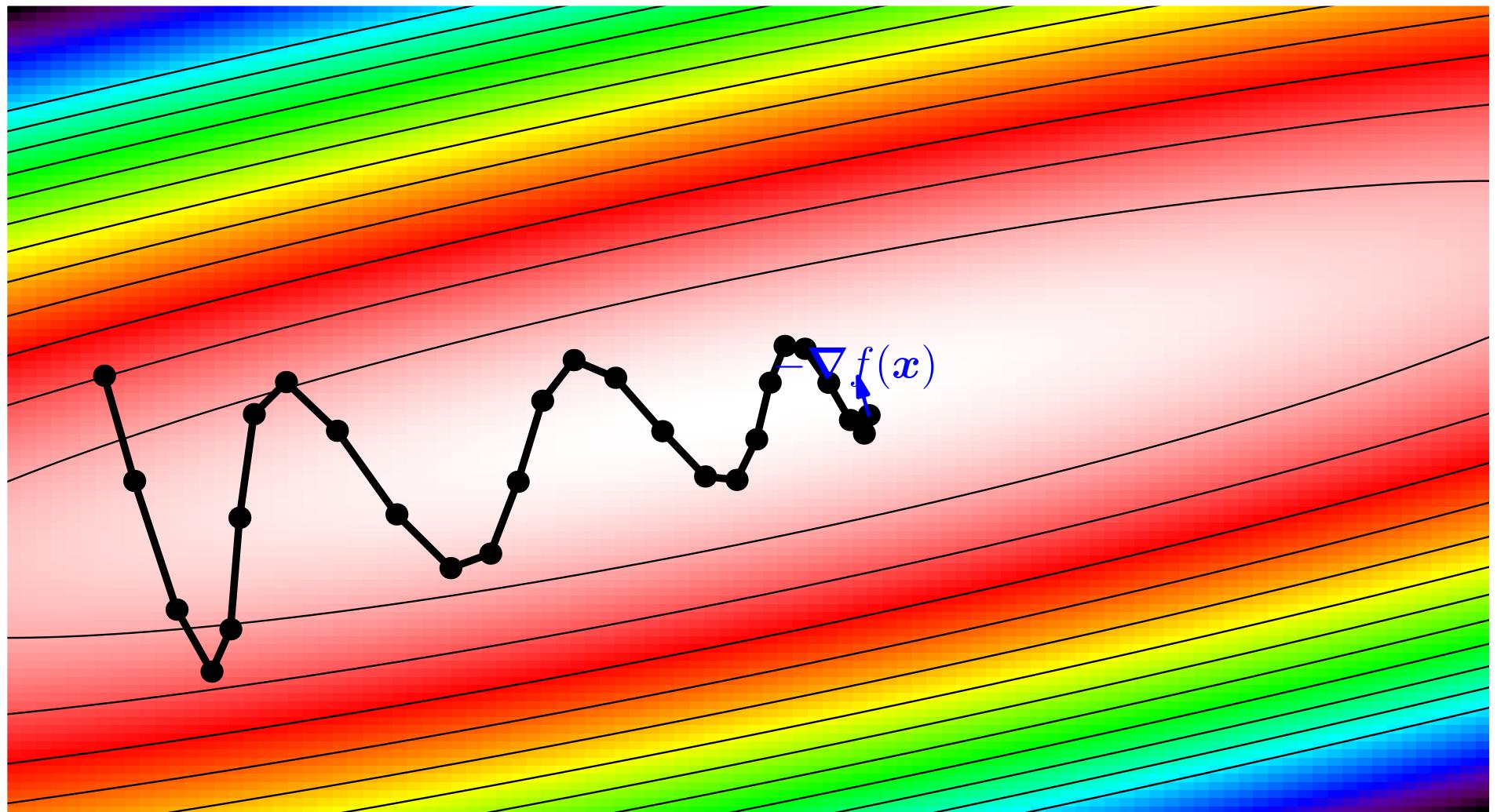
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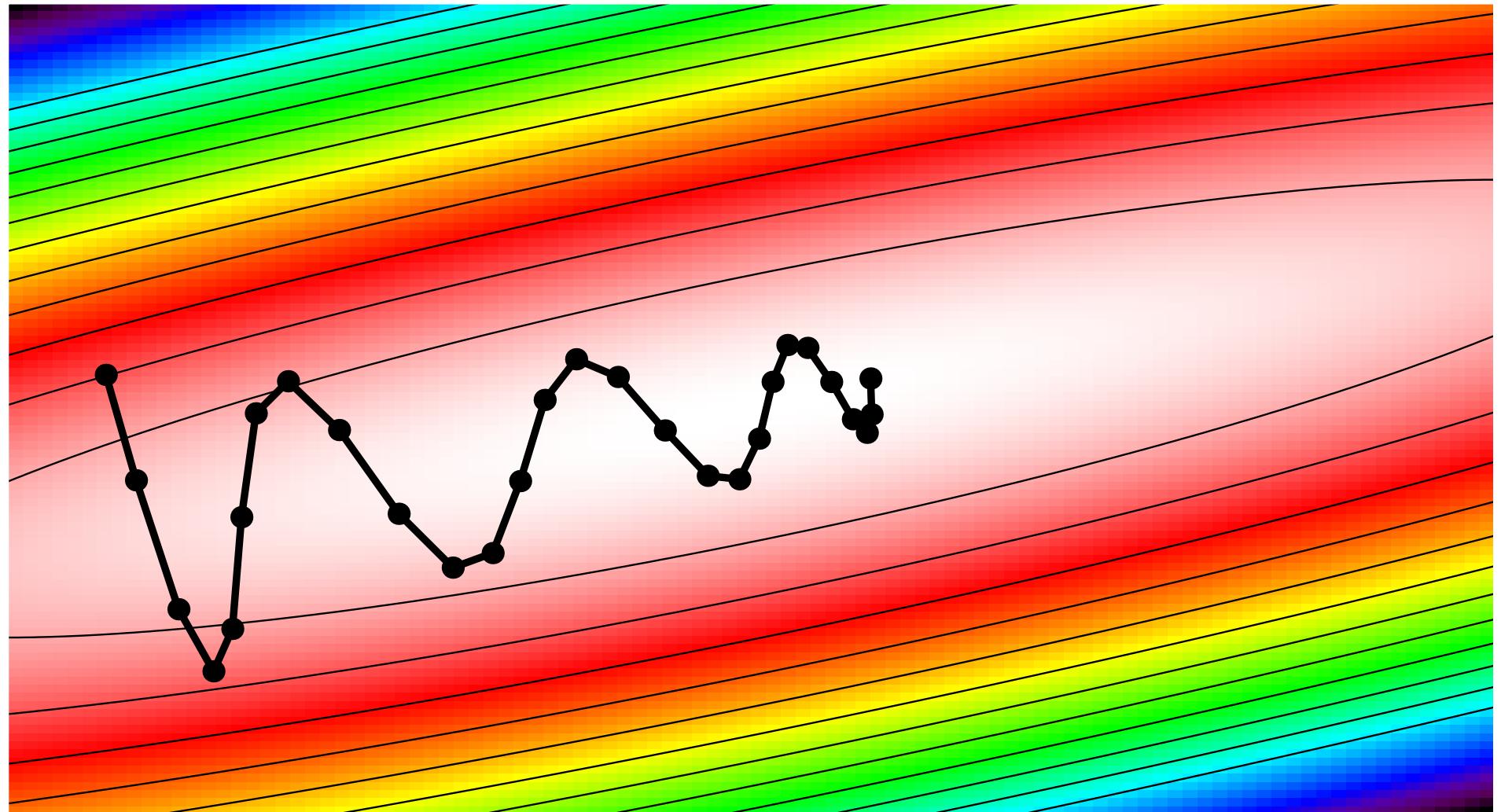
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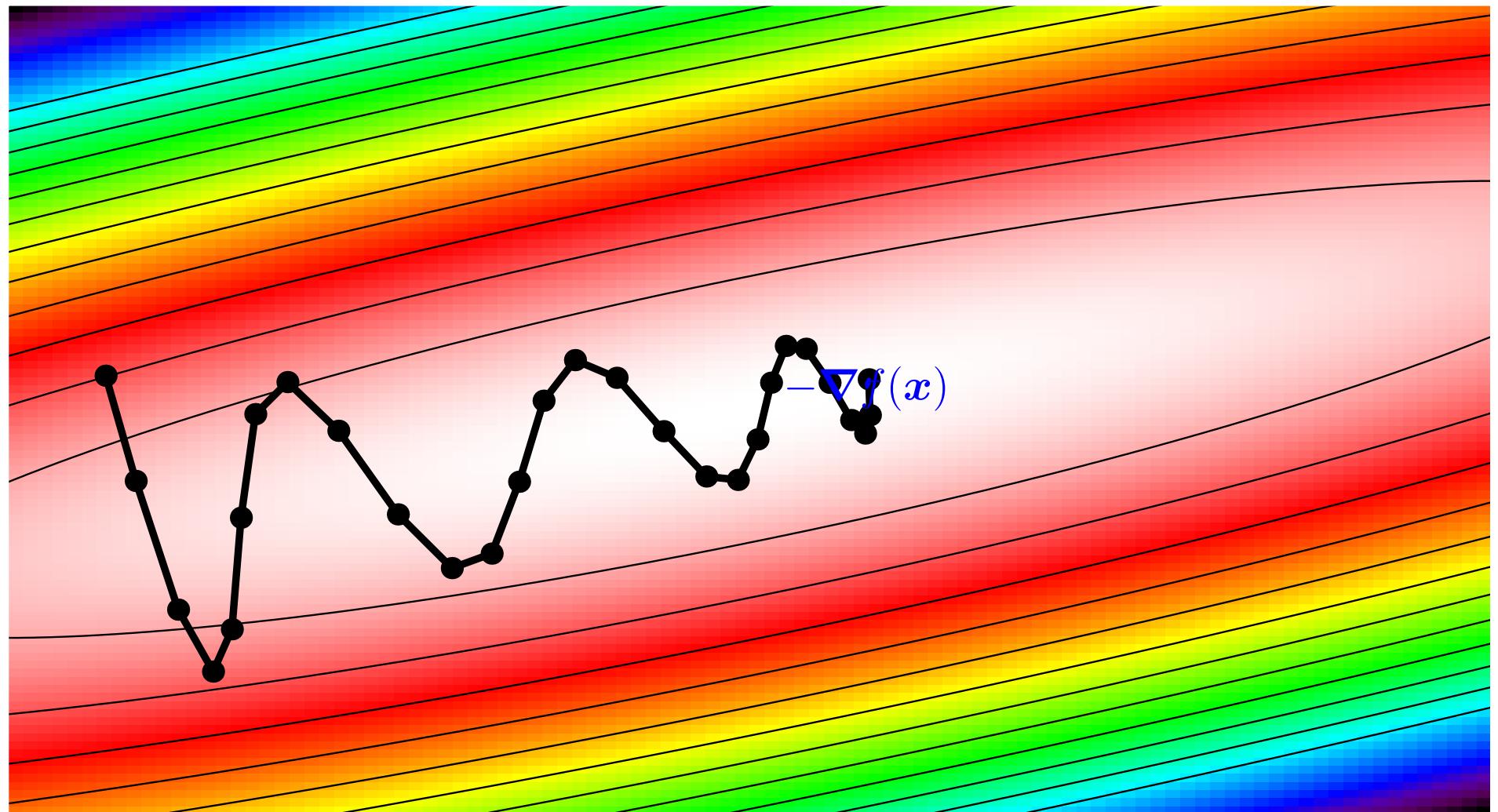
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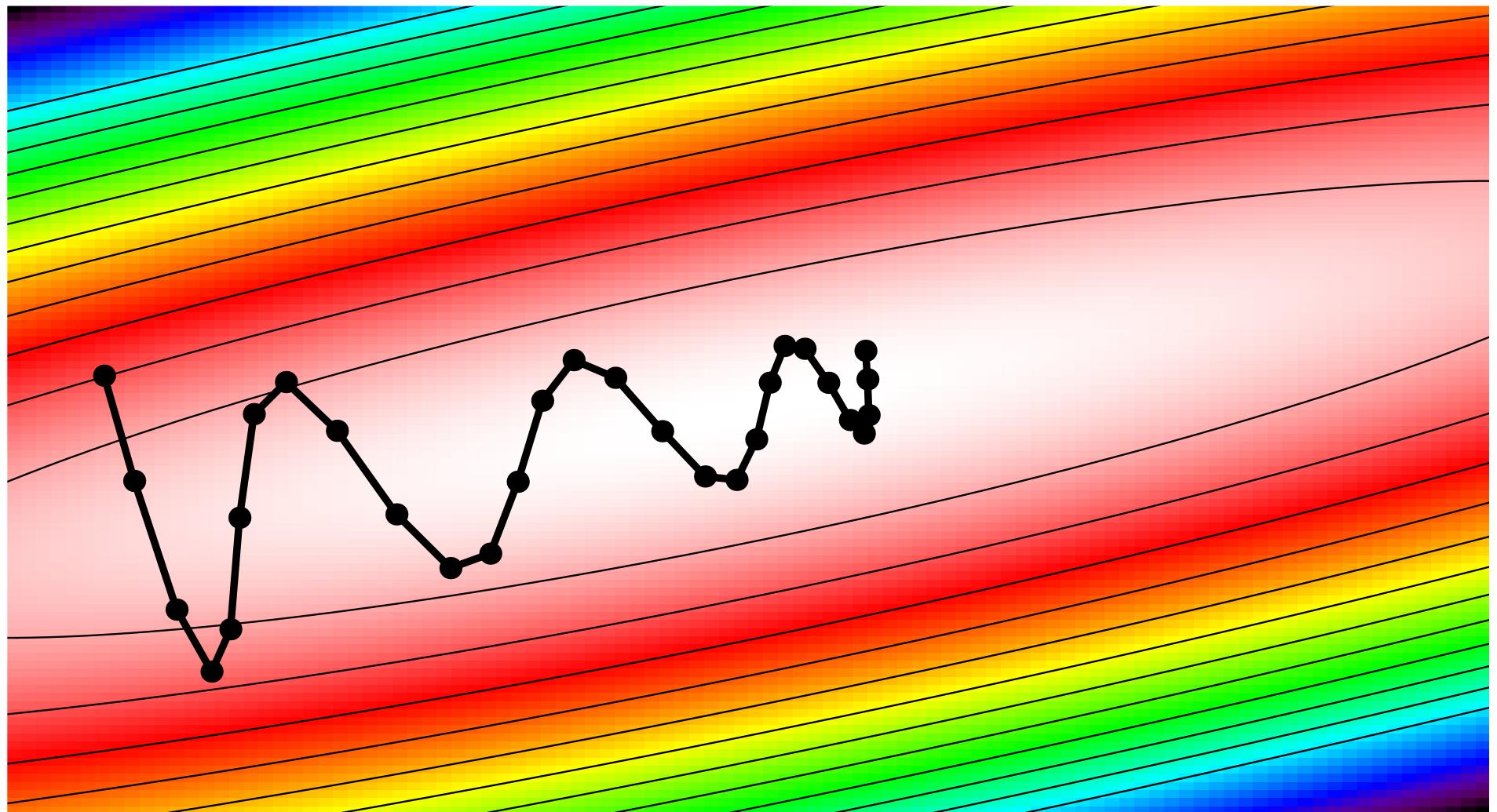
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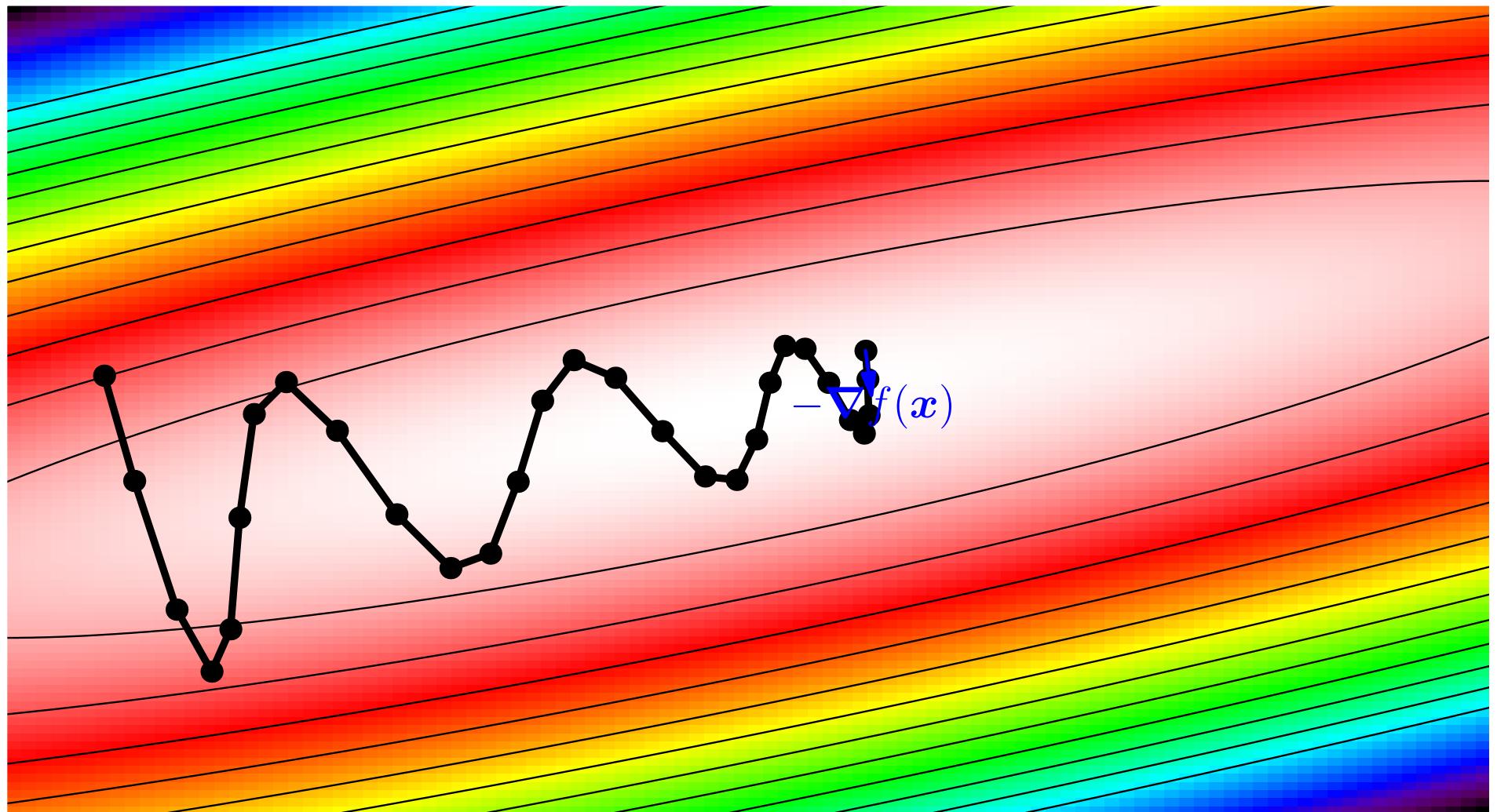
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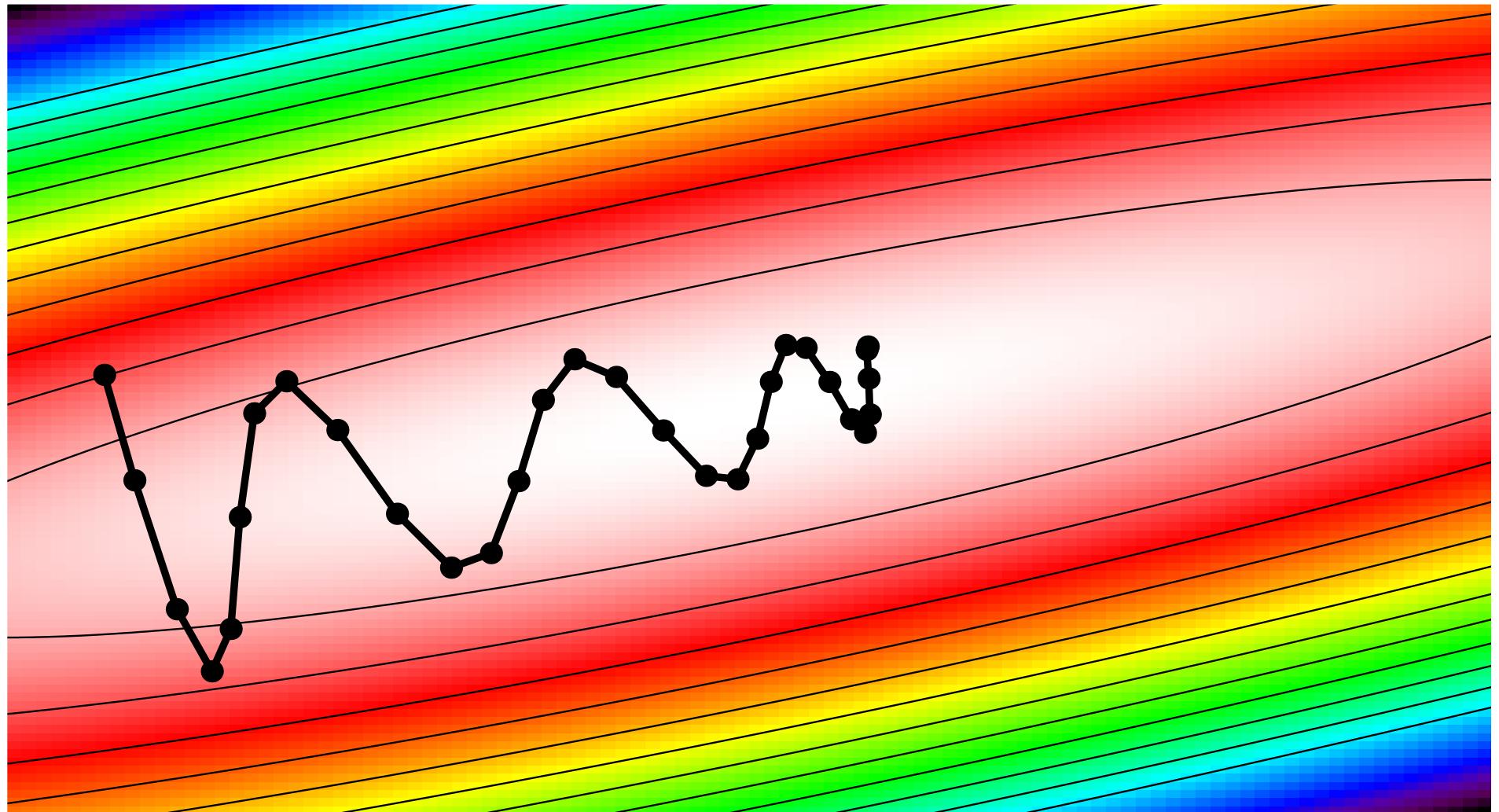
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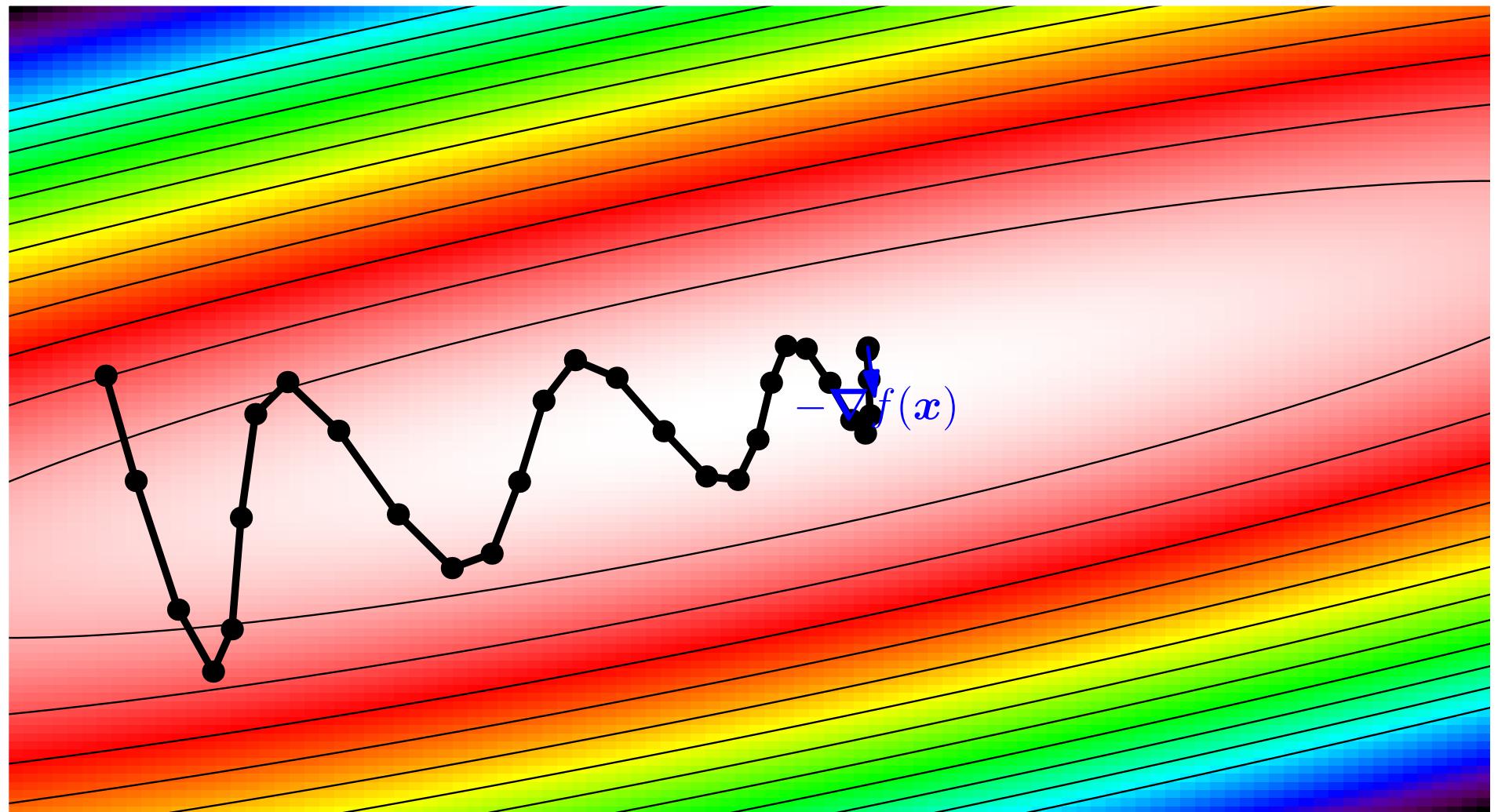
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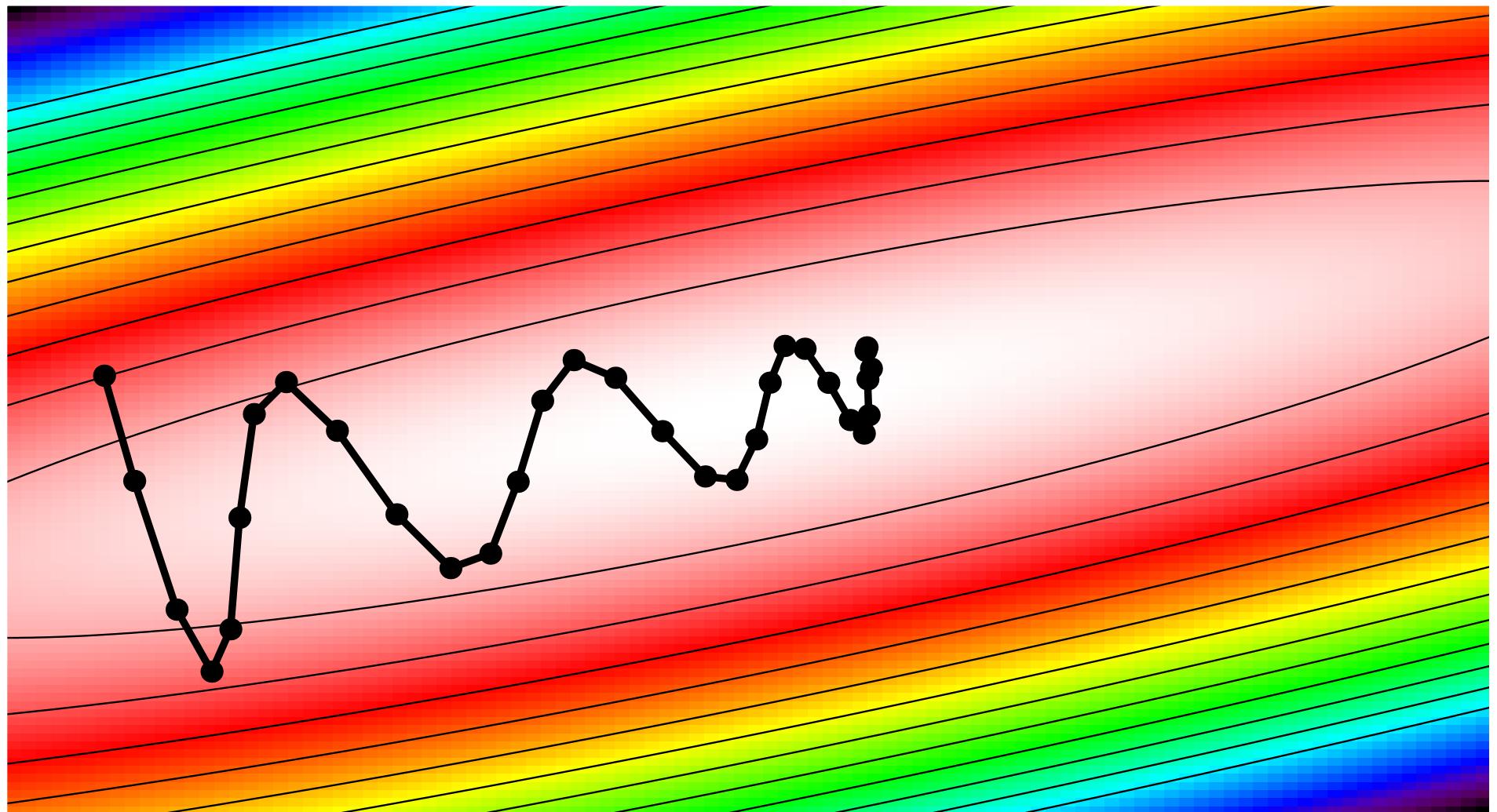
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# Adaptive Methods

- A major difficulty of high dimensional optimisation is the existence of different scales
- That is, there are some directions were we have to move a lot (low curvature), while other directions we have to make small steps
- In adaptive methods we use a dynamic algorithm to rescale the step size of each parameter (weight)
- We can think of this as a “regularisation” that makes our basins of attraction more spherical

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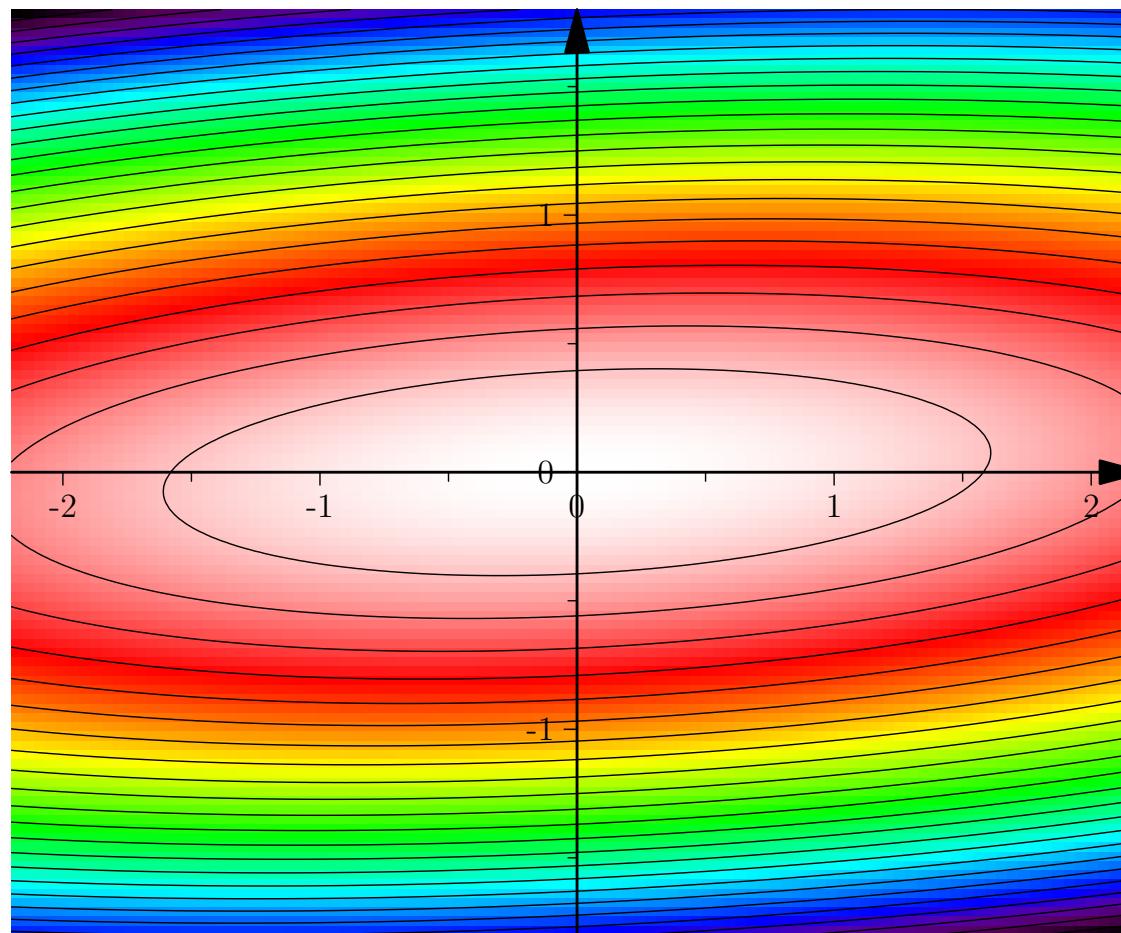
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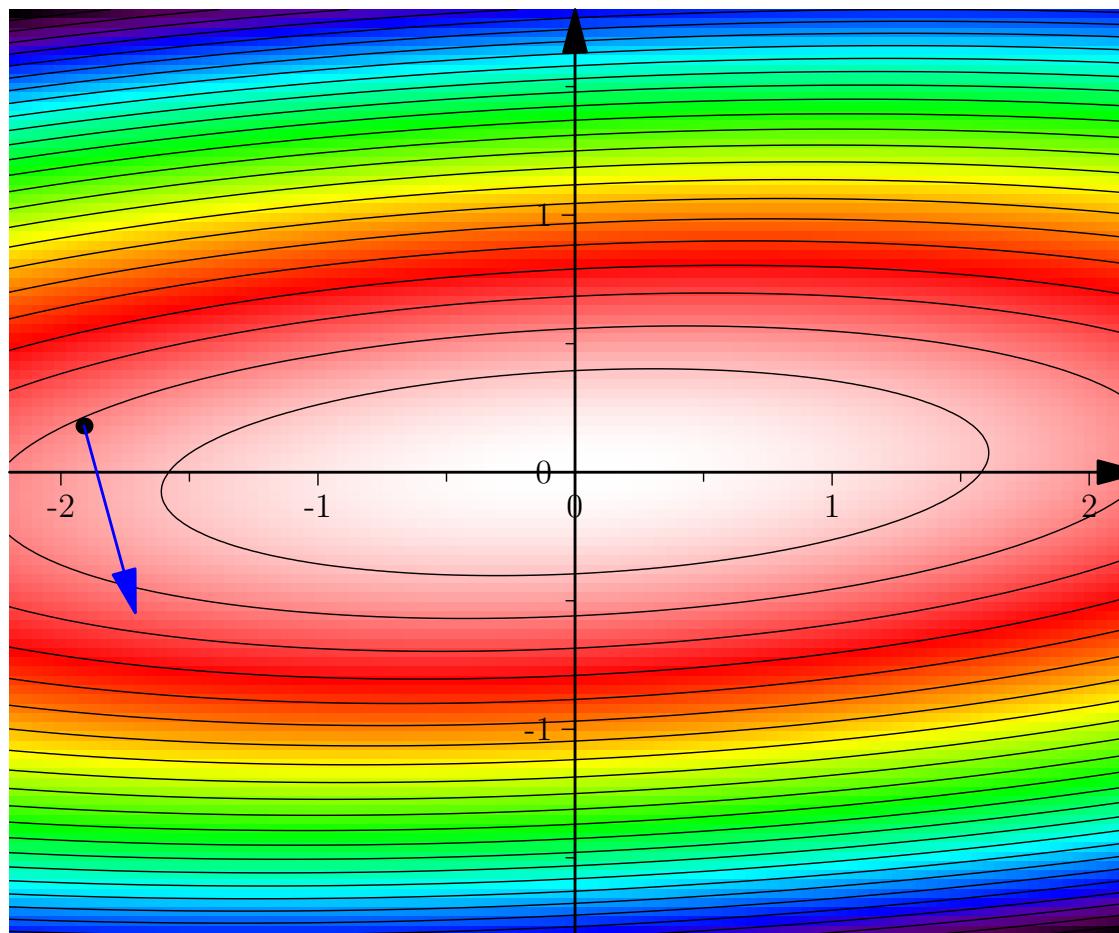
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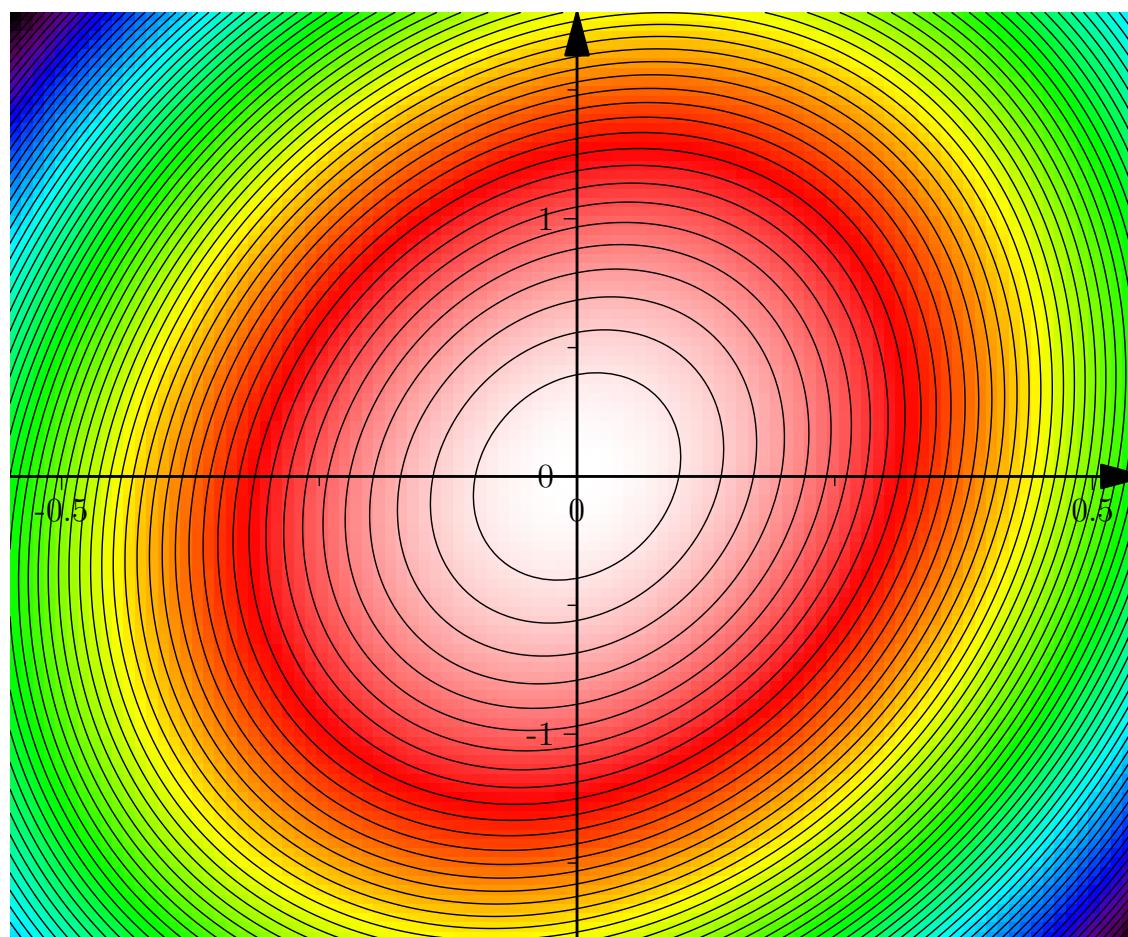
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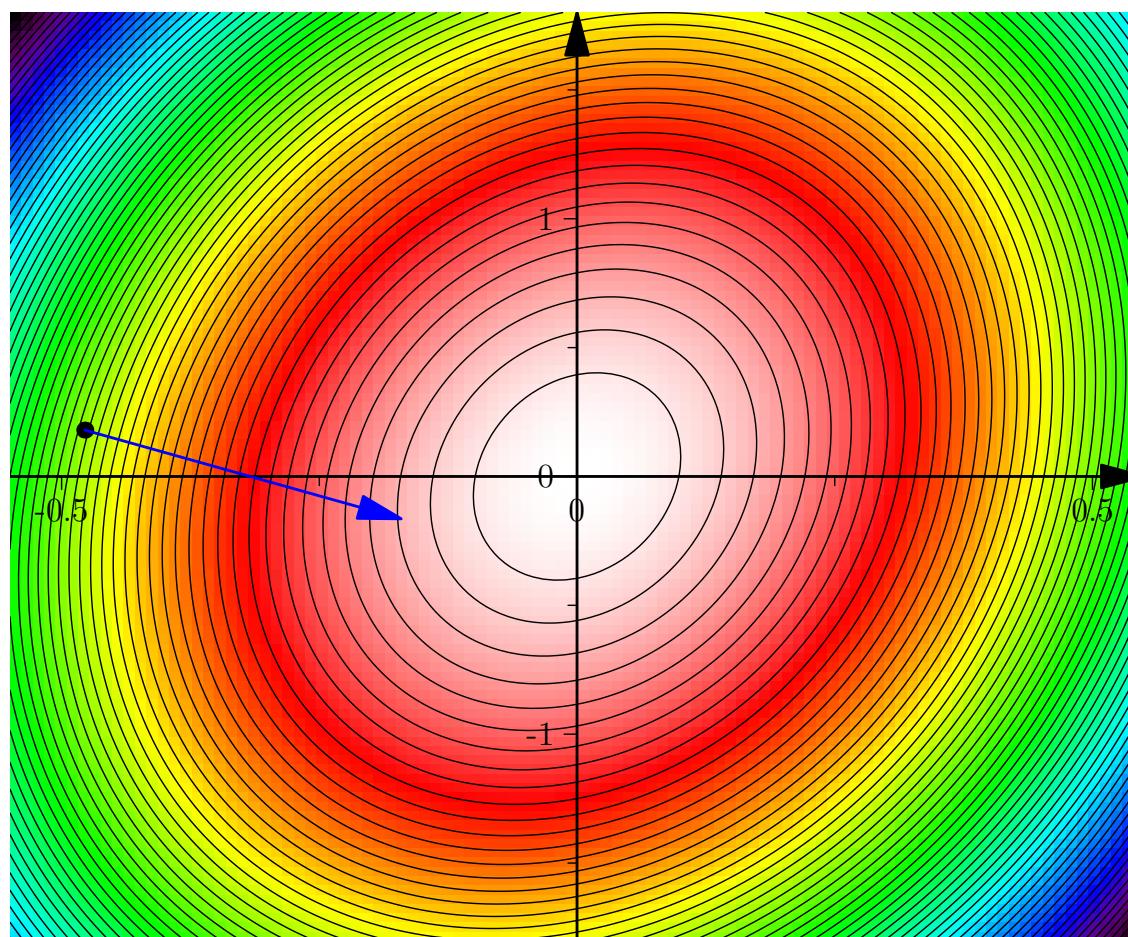
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# AdaDelta

- We want to rescale the coordinates in proportion to the curvature in that direction
- To estimate the curvature we compute a running average of the squared gradients

$$S_i^g(t+1) = (1 - \gamma) S_i^g(t) + \gamma \left( \frac{\partial L_{\mathcal{B}}(\mathbf{w}(t))}{\partial w_i(t)} \right)^2$$

- To estimate the relative scale of the weights we compute a running average of the squared weights

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- Note that we can rescale the weights or rescale the gradients yet the update would be the same
- Because we are adaptively changing our step size we can use a single step size throughout the optimisation

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- Because we are adaptively changing our step size we can use a single step size throughout the optimisation

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- The AdaDelta algorithm uses the update

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# Adding in Momentum

- AdaDelta doesn't use momentum (there is an argument this isn't so important as it has "regularised the landscape")
- Nevertheless we can learn a momentum term

$$M_i(t+1) = (1 - \beta) M_i(t) + \beta \frac{\partial L_{\mathcal{B}}(\mathbf{w}(t))}{\partial w_i(t)}$$

$$S_i(t+1) = (1 - \gamma) S_i(t) + \gamma \left( \frac{\partial L_{\mathcal{B}}(\mathbf{w}(t))}{\partial w_i(t)} \right)^2$$

- These running averages have a lag time which we can remove

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# ADAM

- Adaptive Moment Estimation (Adam) adapts the scale of the parameters, but also uses momentum
- Update weights

$$w_i(t + 1) = w_i(t) - \frac{\eta}{\sqrt{\hat{S}_i(t + 1)} + \epsilon} \hat{M}_i(t + 1)$$

- ADAM and its variants are very successful in deep learning
- It is very robust so often results in a network learning which might not learn under standard SGD (with momentum)

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# Covariant Equations

- Vector arithmetic, (matrix multiplication, addition, multiplying by a scale, computing gradients) has a covariant property that it is invariant to the coordinate system
- That is we can translate and rotate our coordinates and get the same result
- That is not true of element-wise multiplication of vectors
- Many ML algorithms do this (including ADAM and adaDelta), but they aren't invariant if we rotate our coordinates

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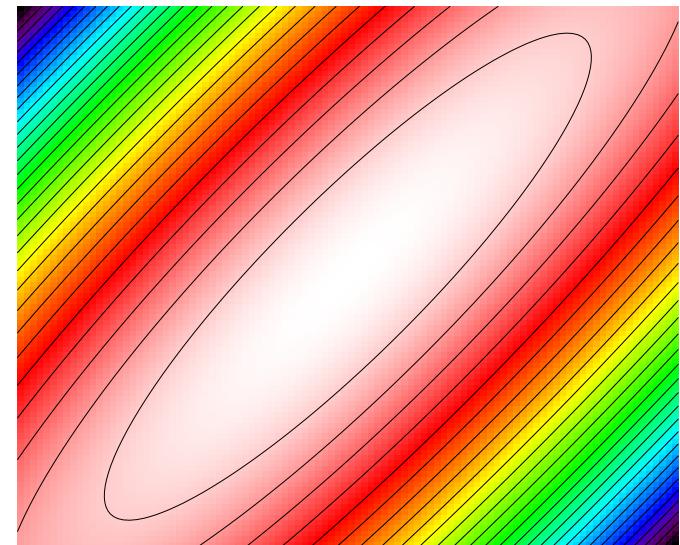
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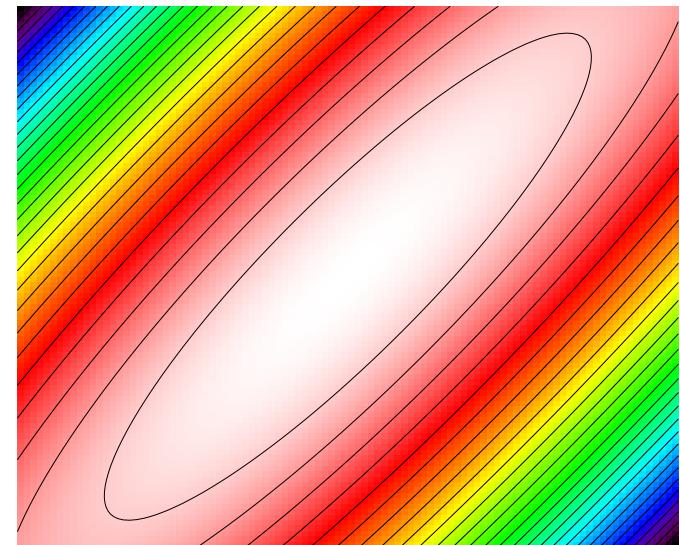
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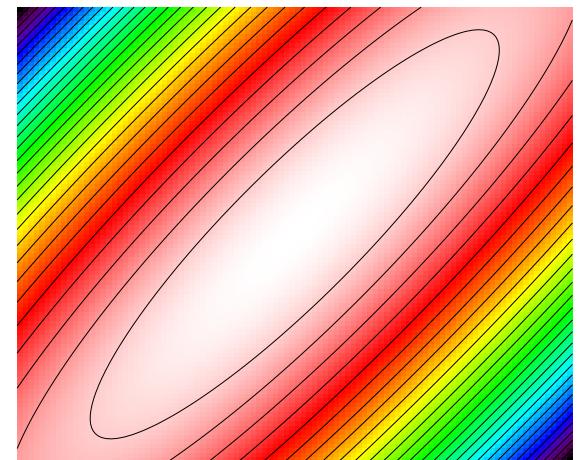
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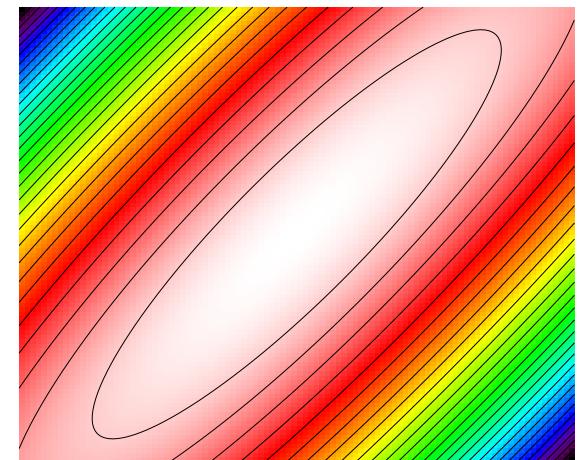
# Correlated Weights

- Correlated weights will lead to skewed valleys
- Adaptive methods would be more efficient if they were rotationally invariant
- However, this would slow down the algorithm
- ADAM is a compromise between speed of implementation and effectiveness



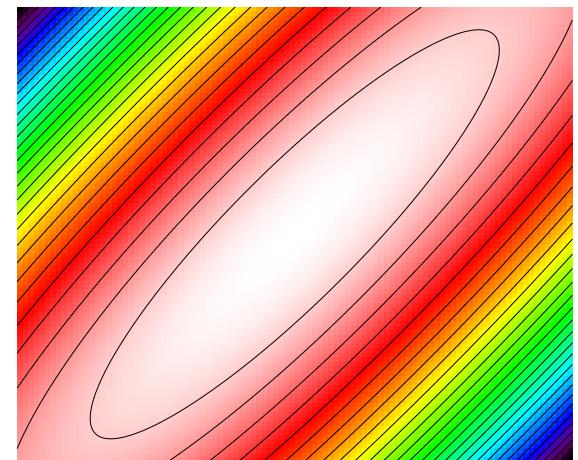
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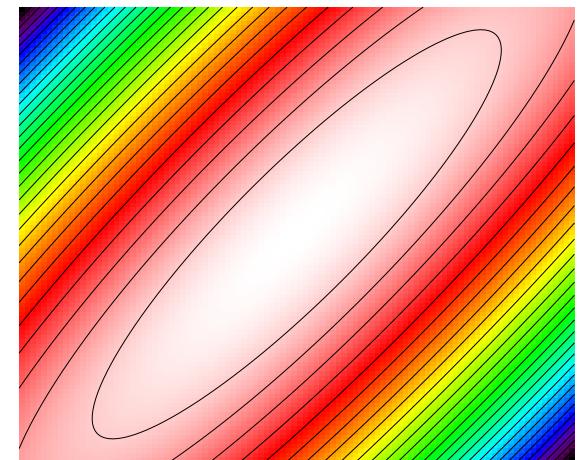
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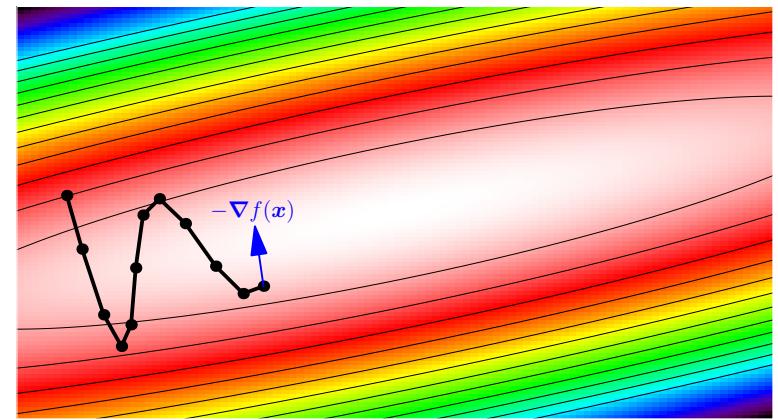
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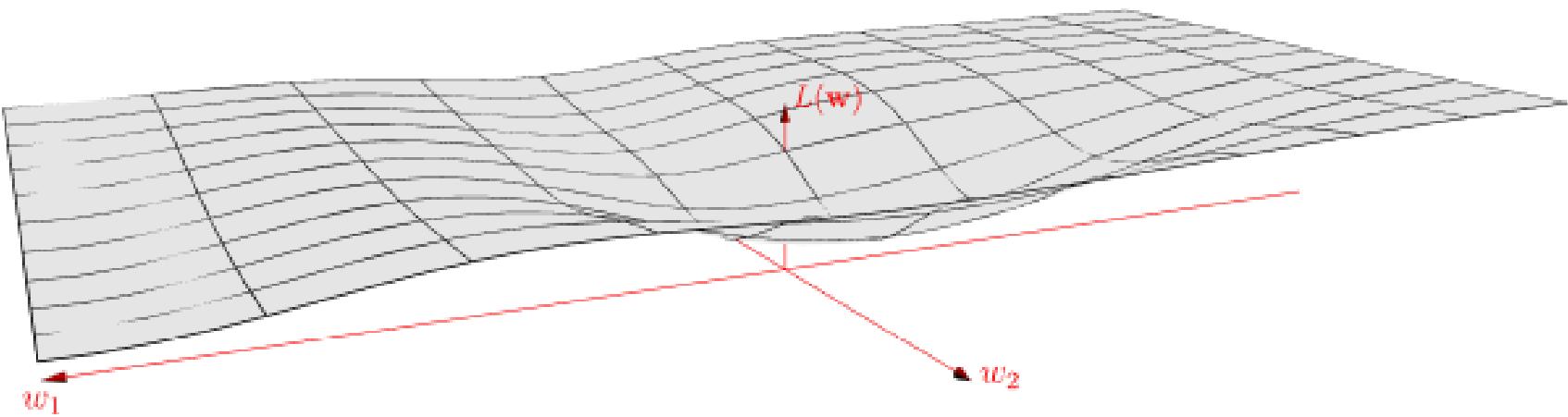
# Outline

1. SGD
2. Momentum
3. Loss Landscapes



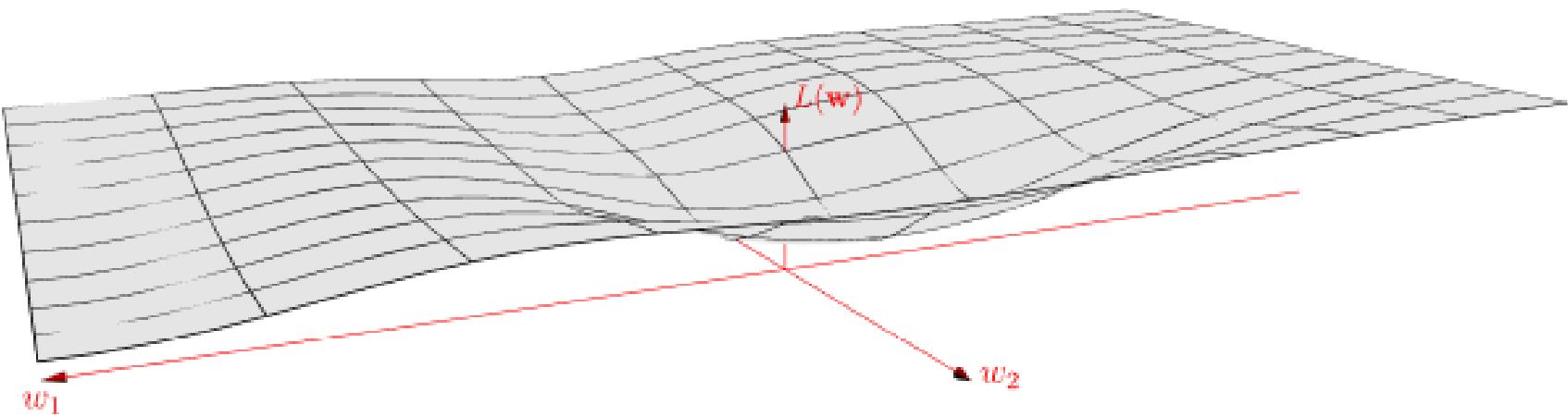
# Loss Landscape

- A useful concept for understanding optimisation is the loss landscape
- For every value of the weights  $w$  there is some loss associated with it
- Note that this landscape is very high dimensional, so our intuition can be a bit misleading
- The landscape is also huge



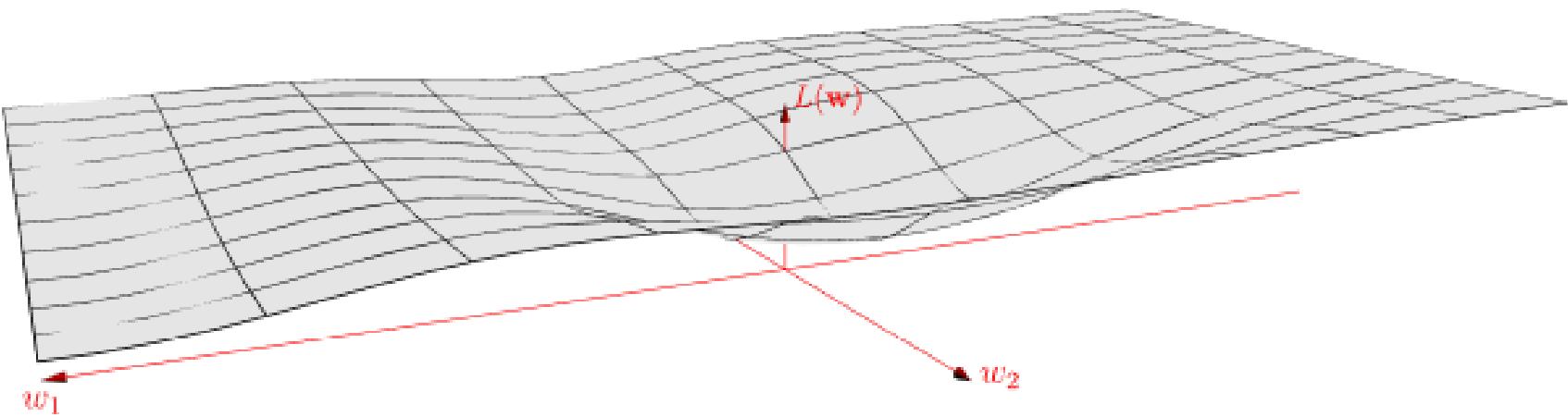
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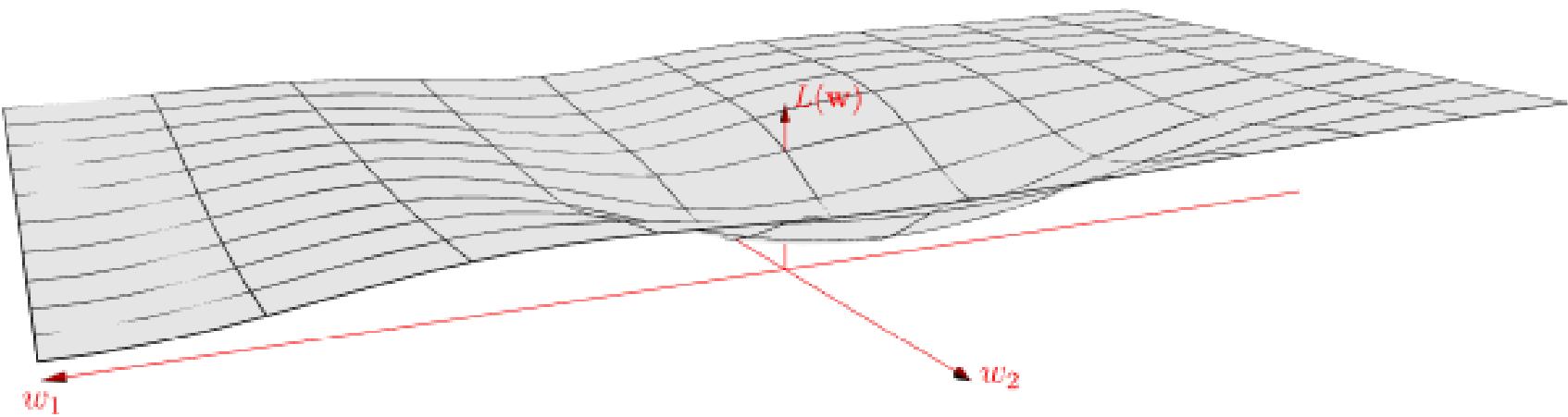
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- Our objective is to minimise our loss
- This would mean finding the global minimum
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- The best we can hope is to find a local minimum by doing gradient descent
- In practice, our landscapes are so large that we are probably unable to find even a local minimum

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- Because we are using mini-batches we aren't actually following the correct gradients
- If we reduce our step size then our average gradient is closer to the true gradient
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- My view of the loss landscape is that we have valleys inside bigger valleys inside bigger valleys, and so on
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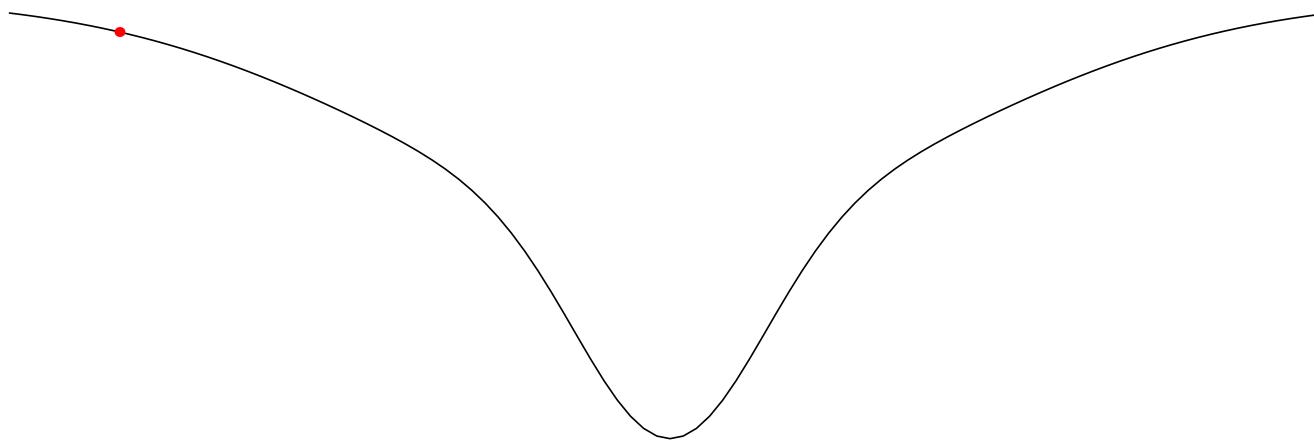
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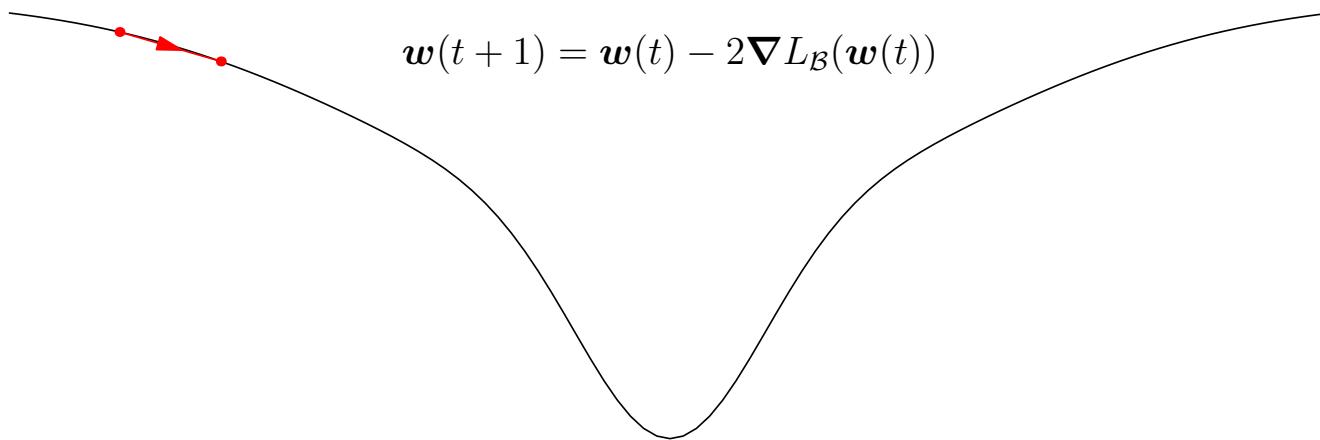
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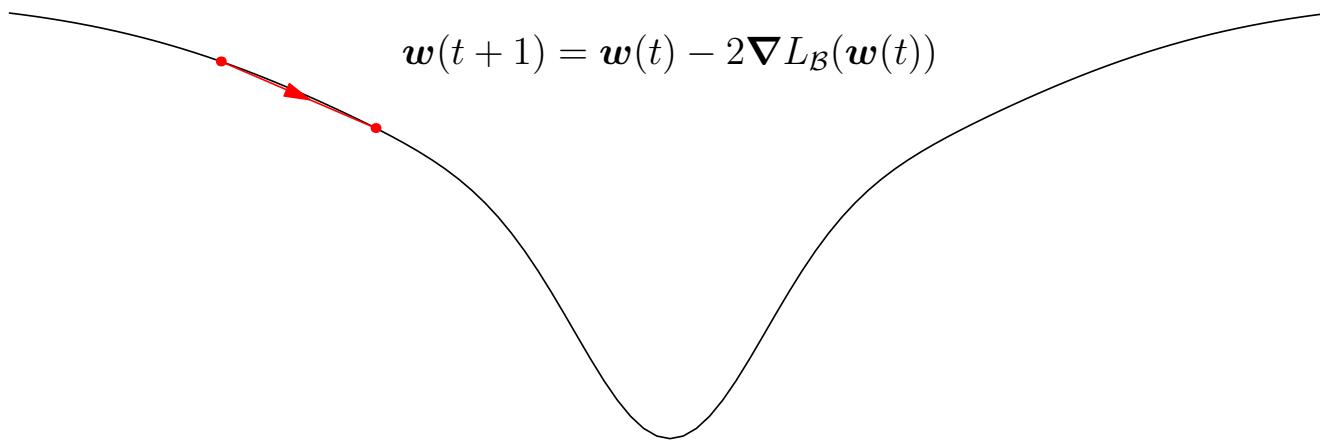
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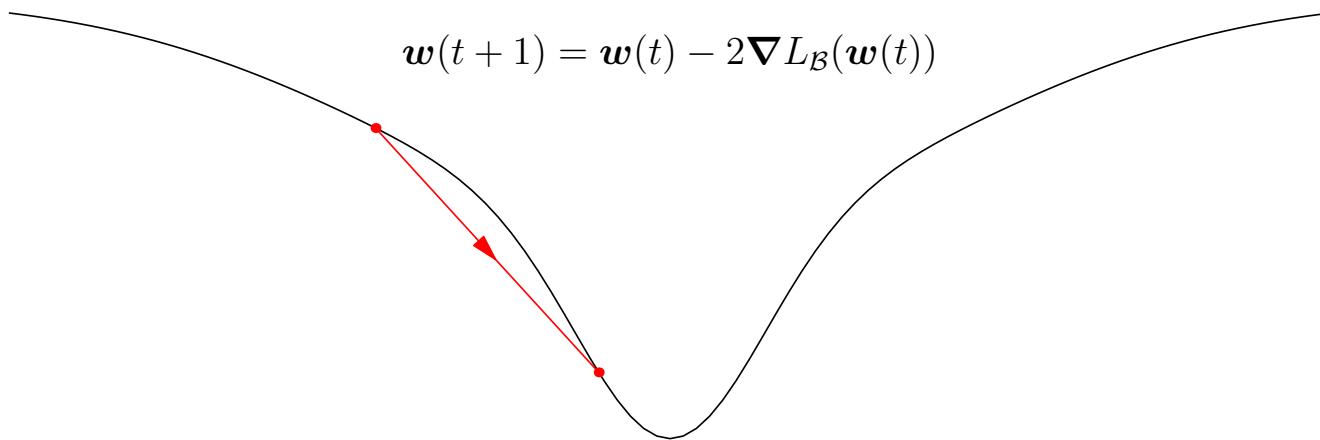
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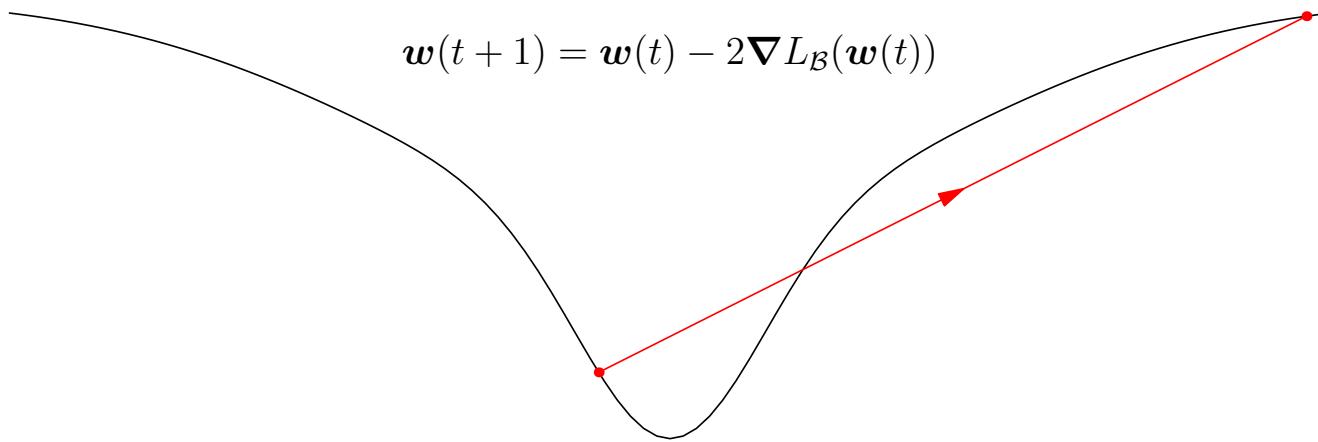
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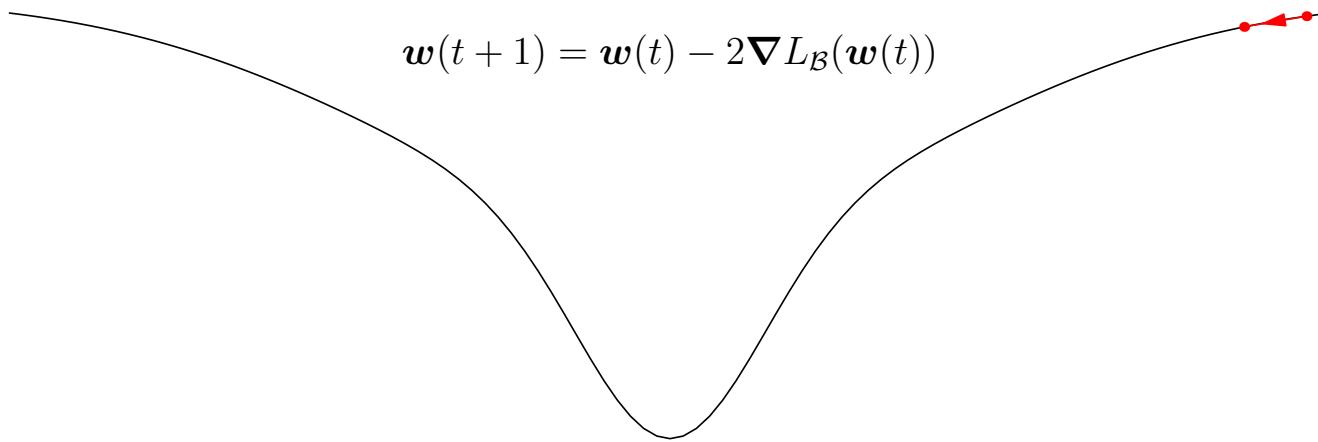
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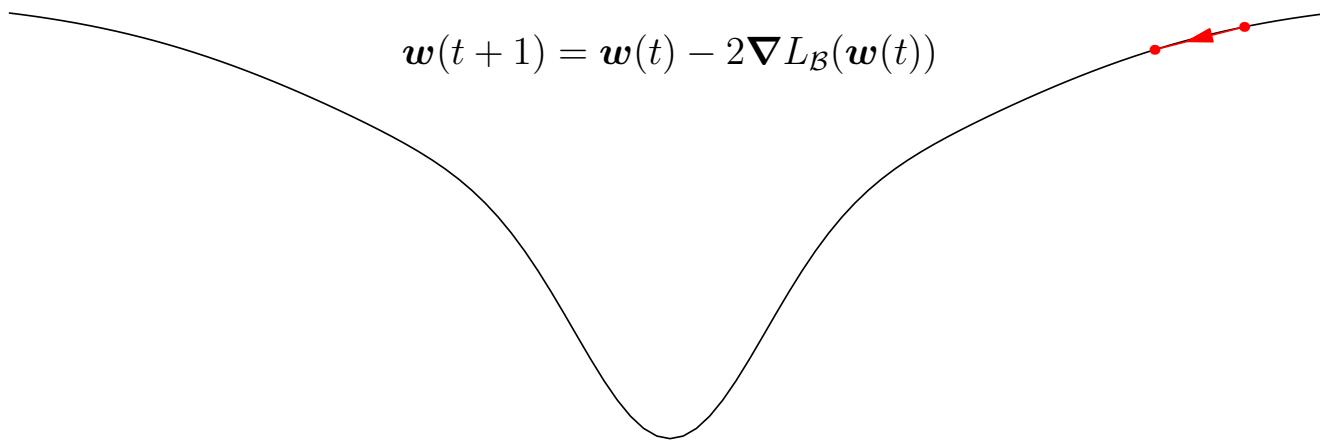
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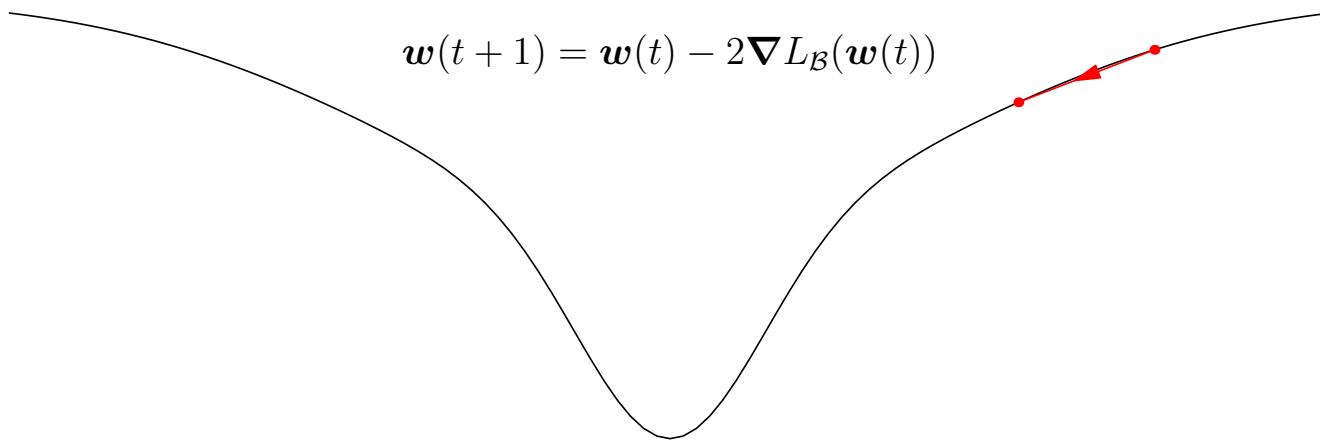
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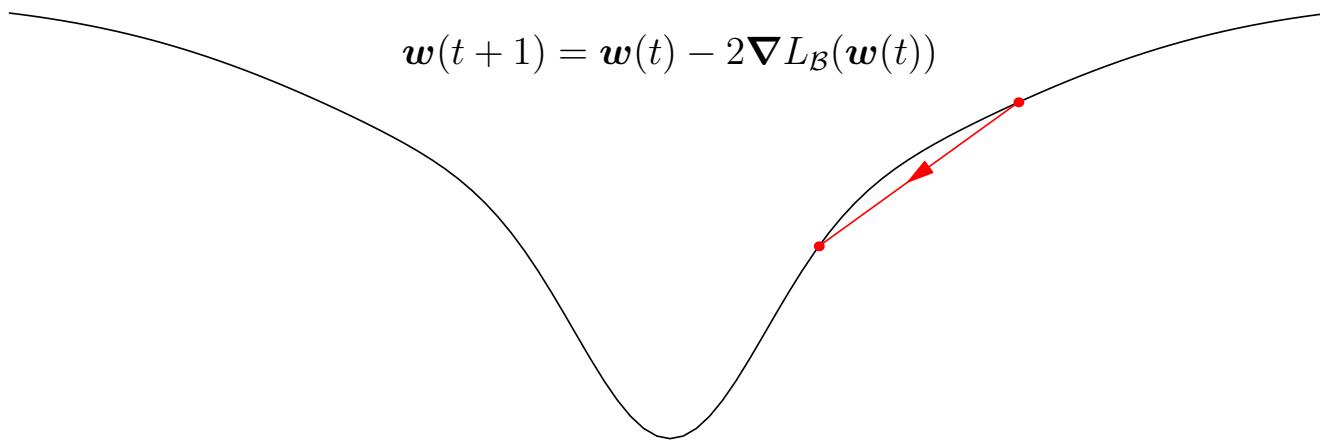
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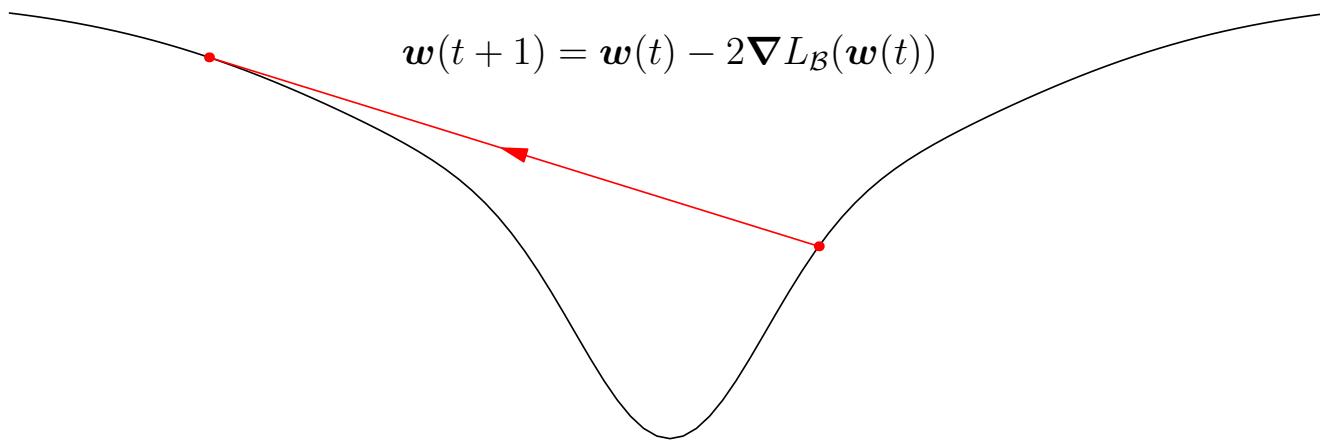
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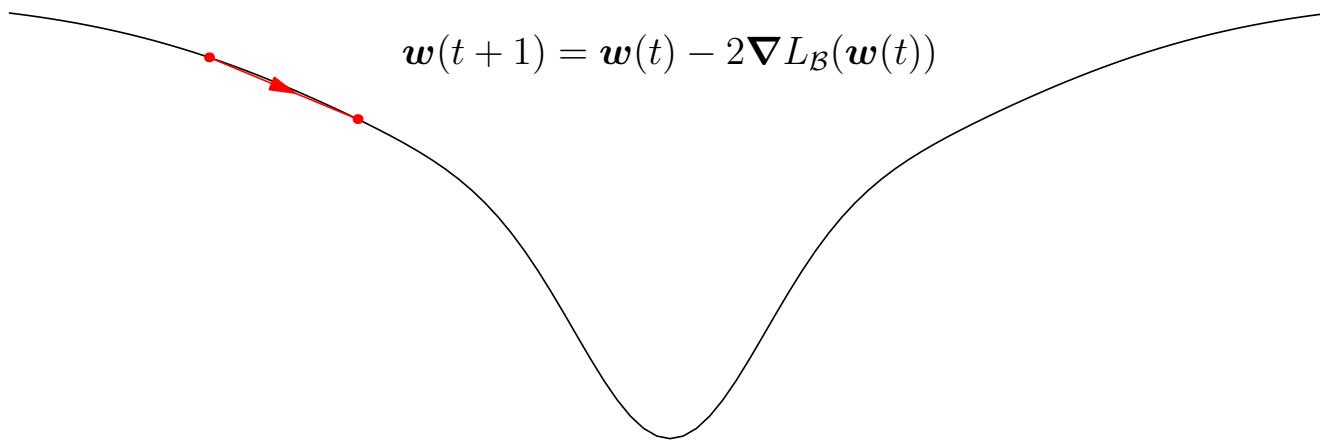
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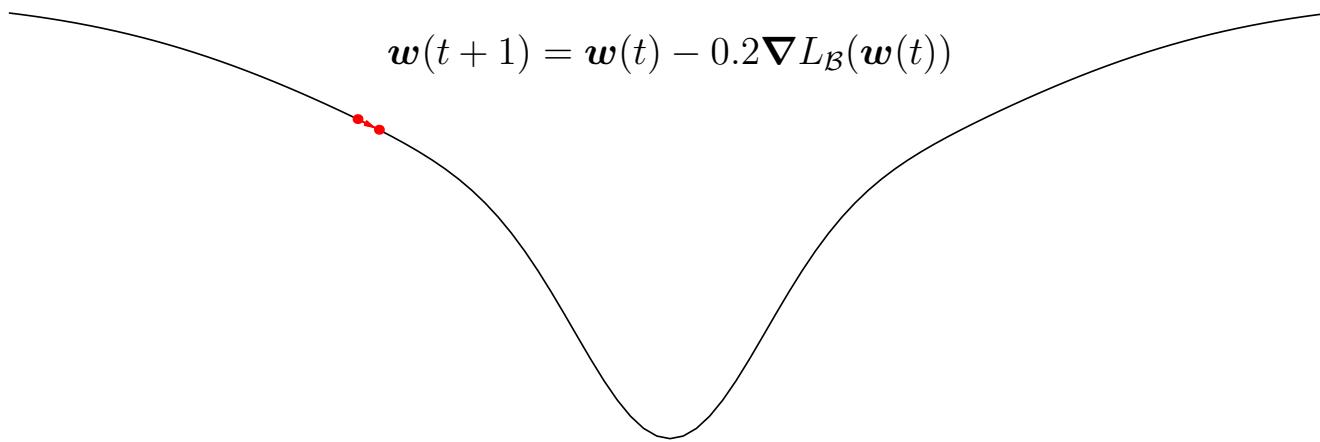
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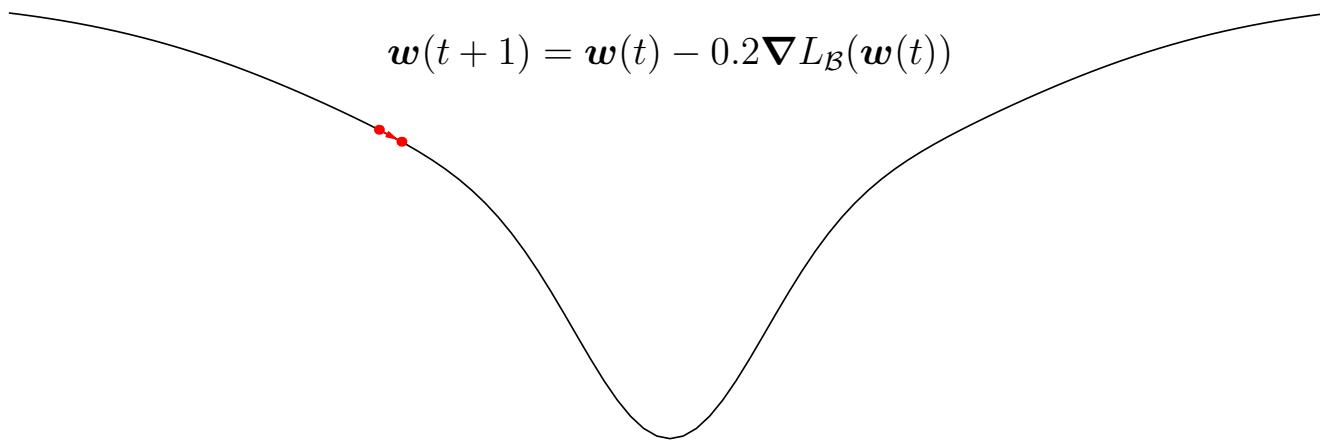
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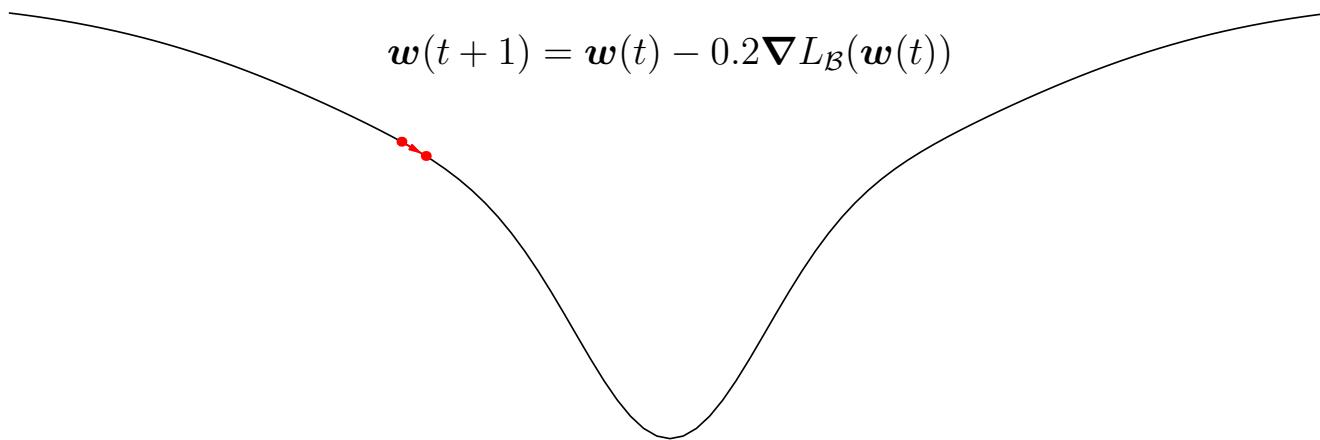
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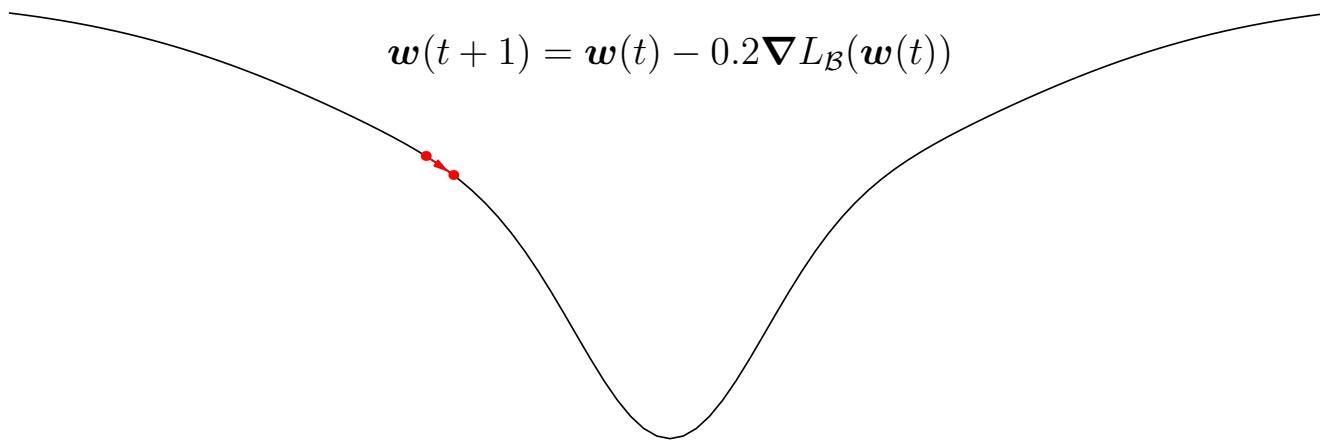
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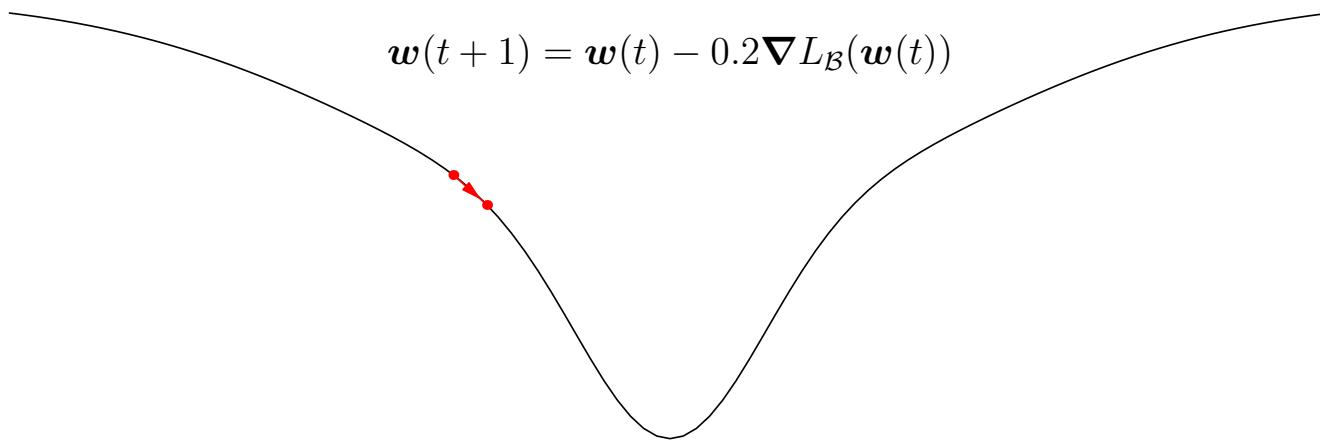
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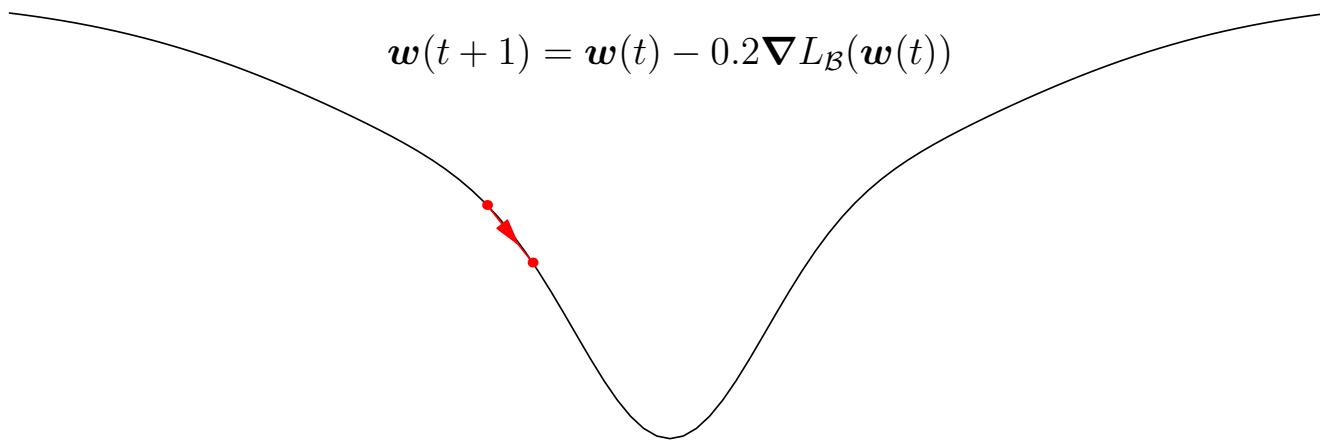
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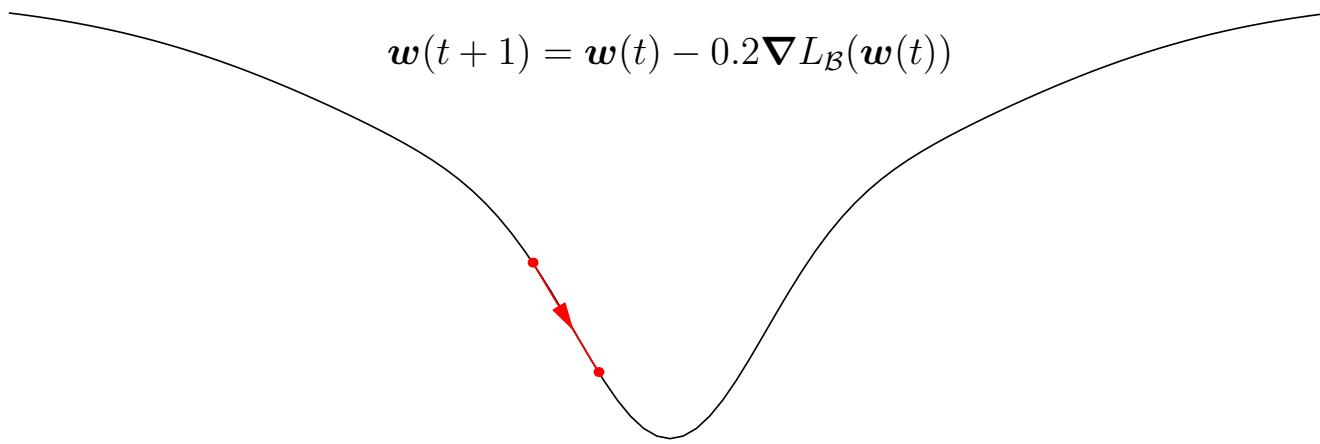
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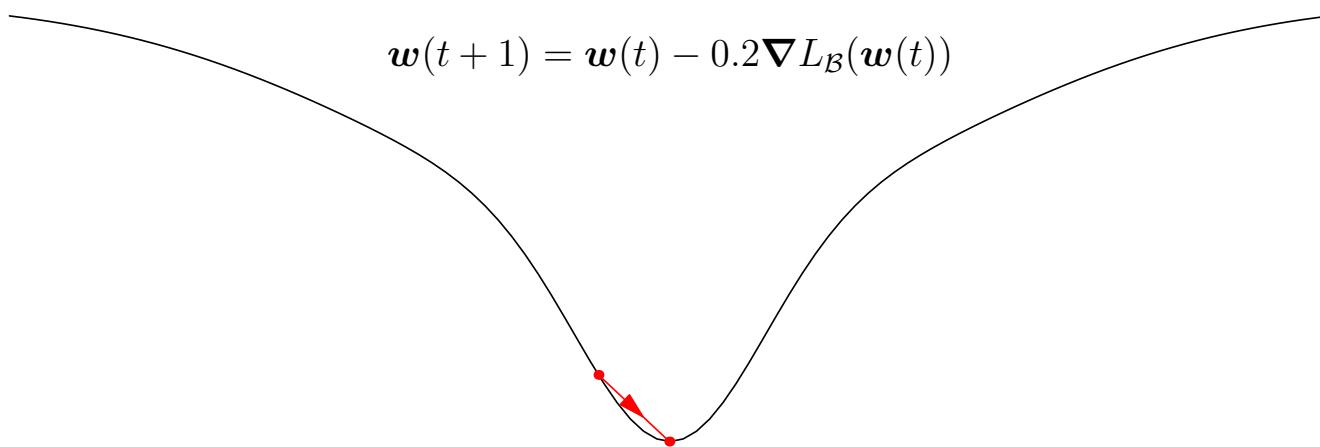
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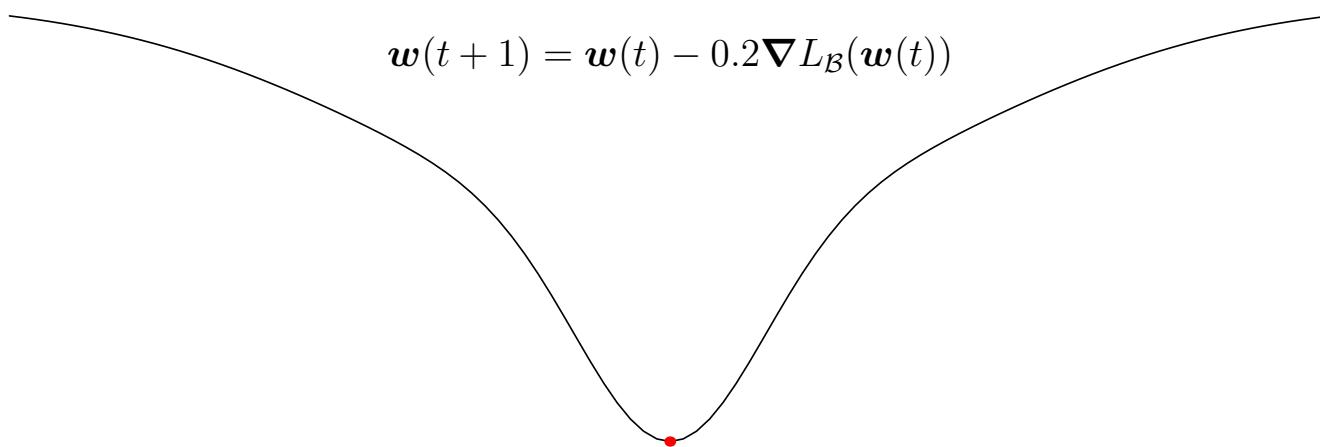
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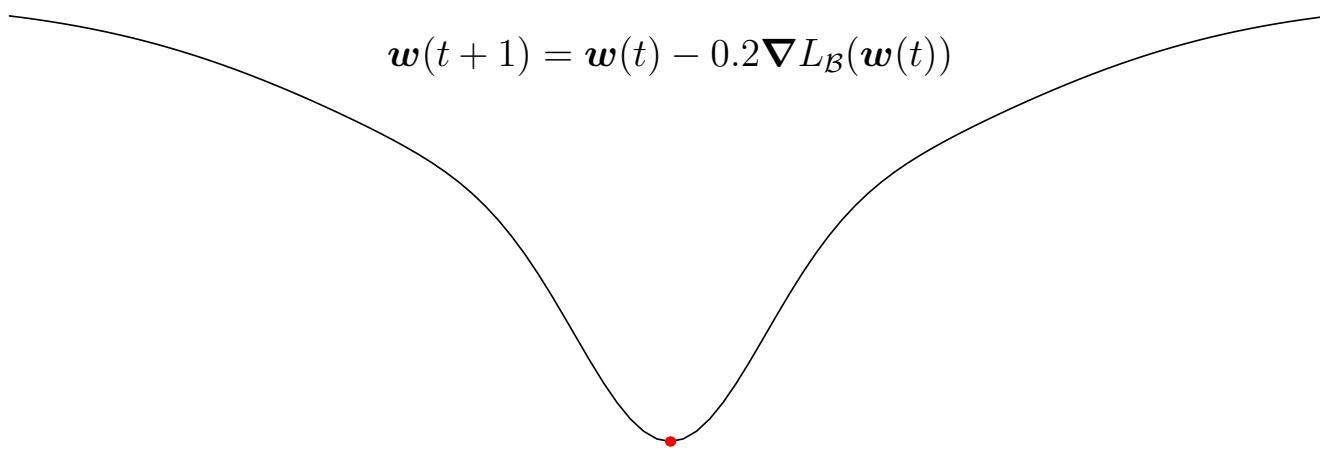
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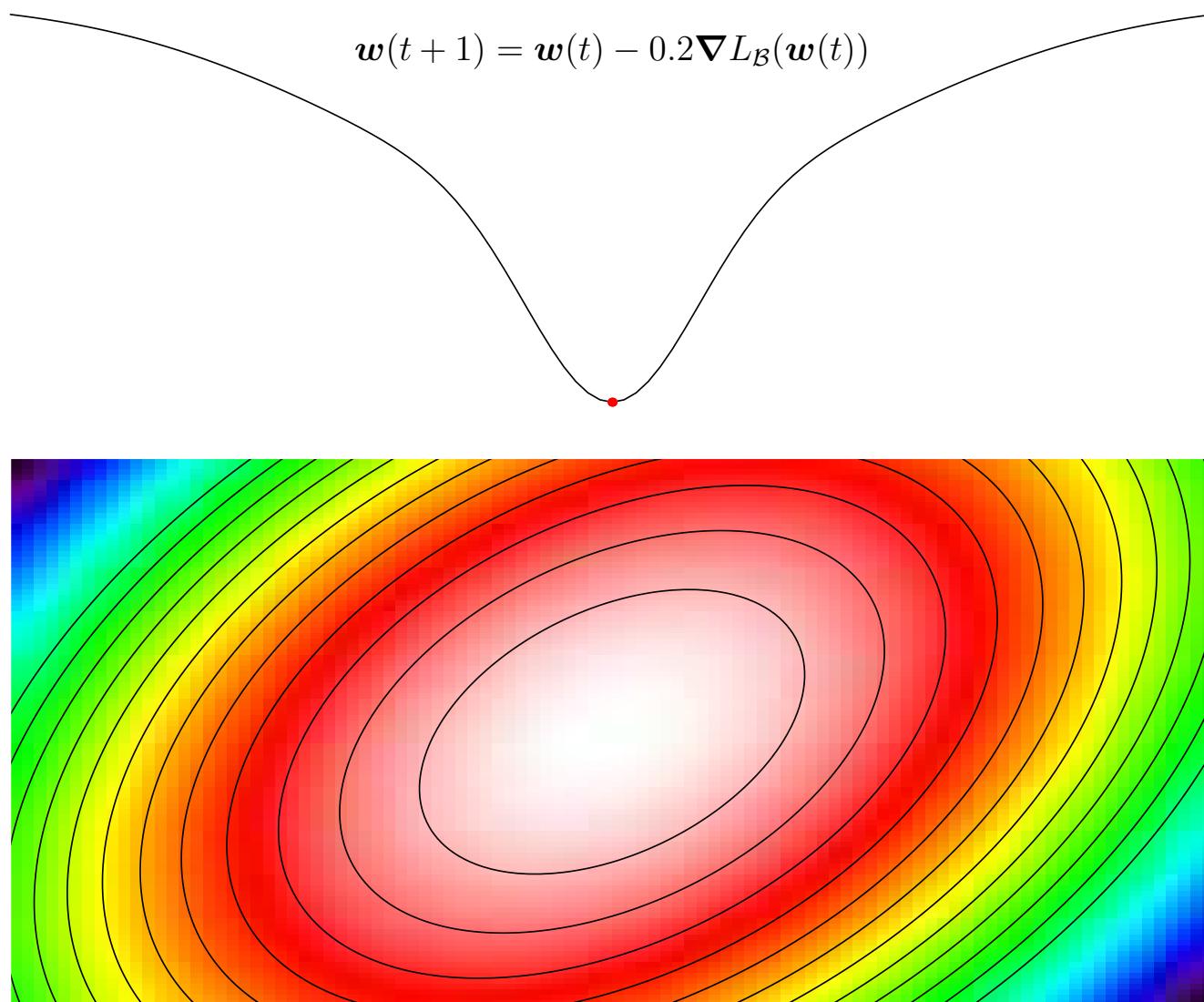
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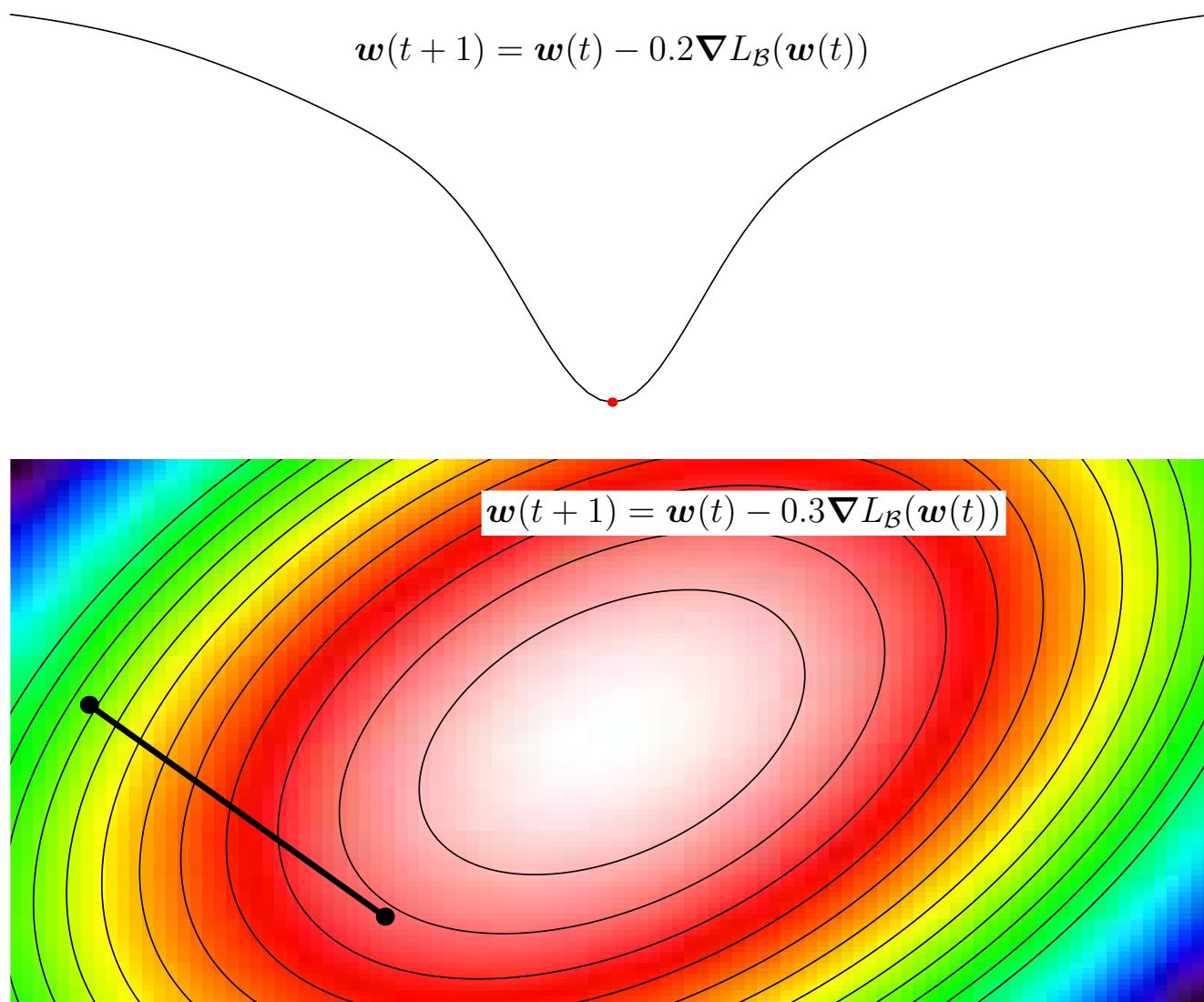
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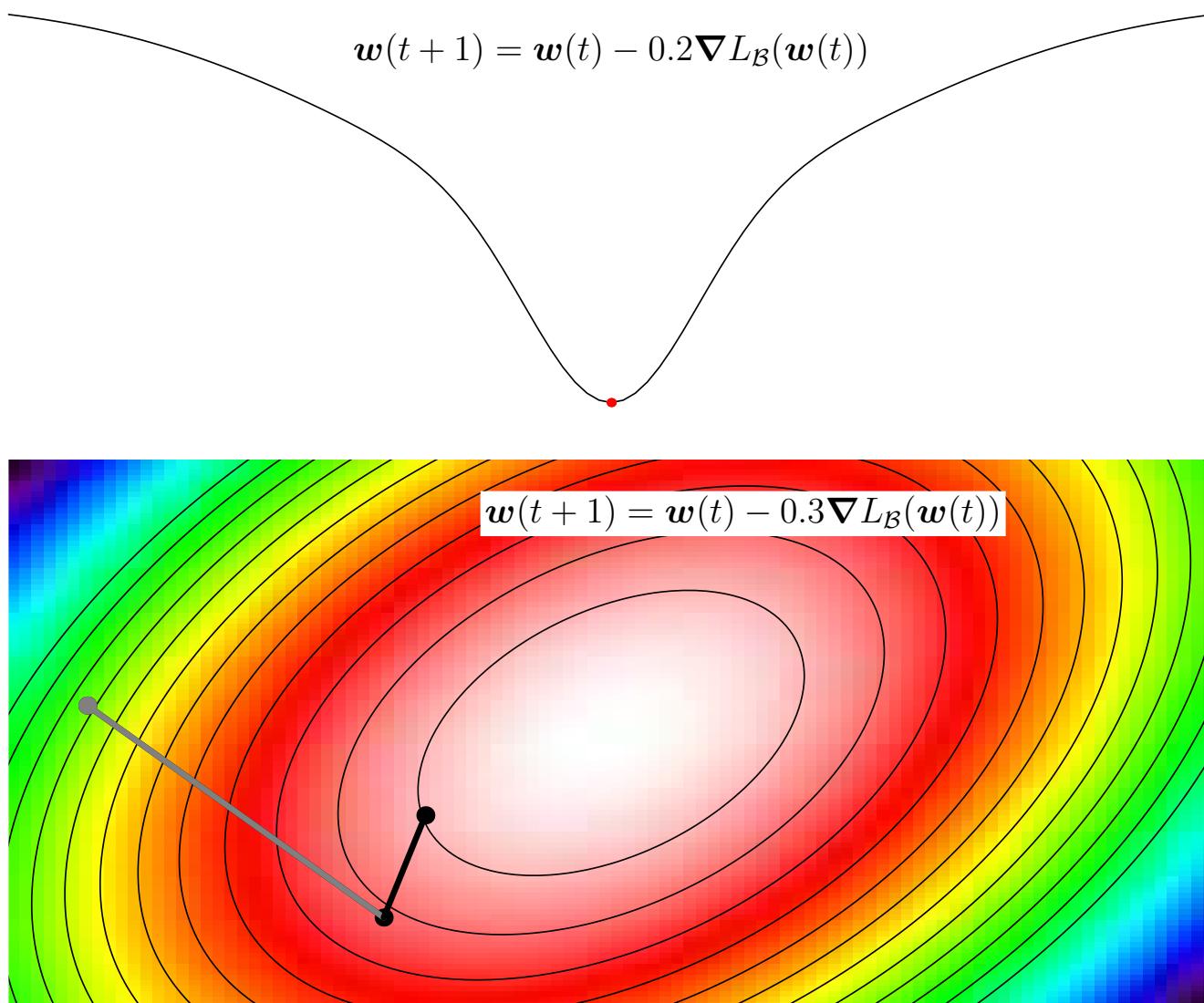
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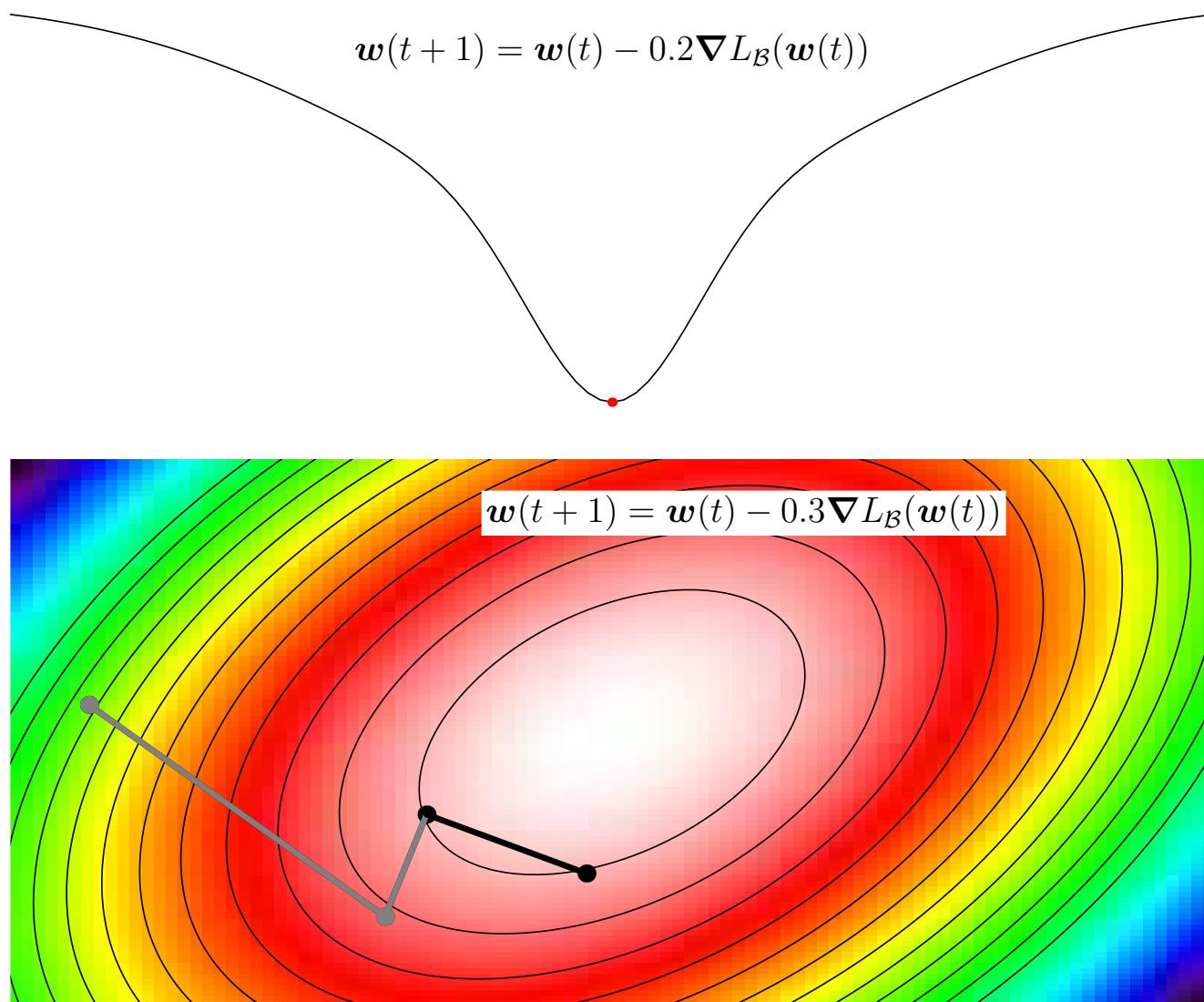
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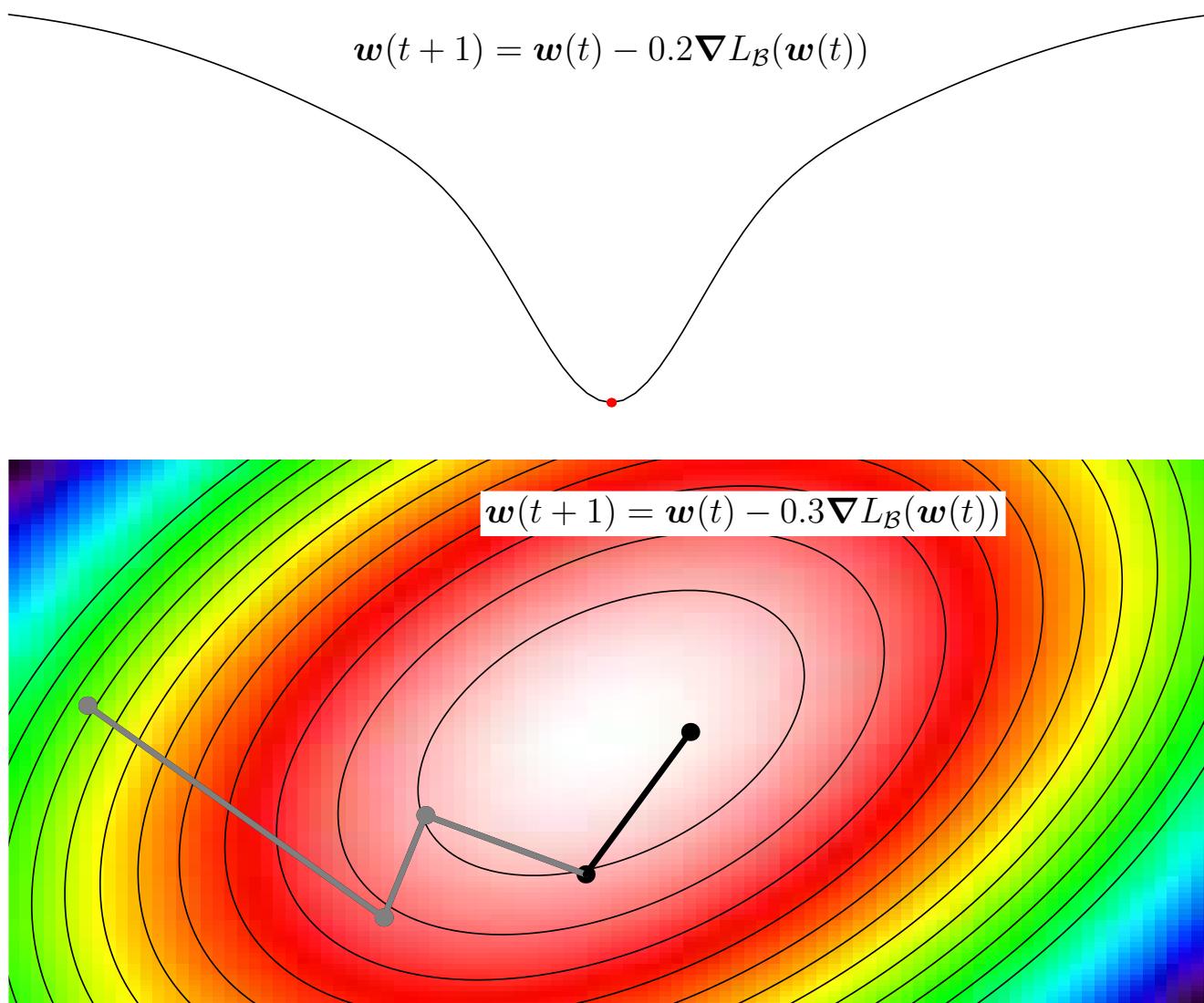
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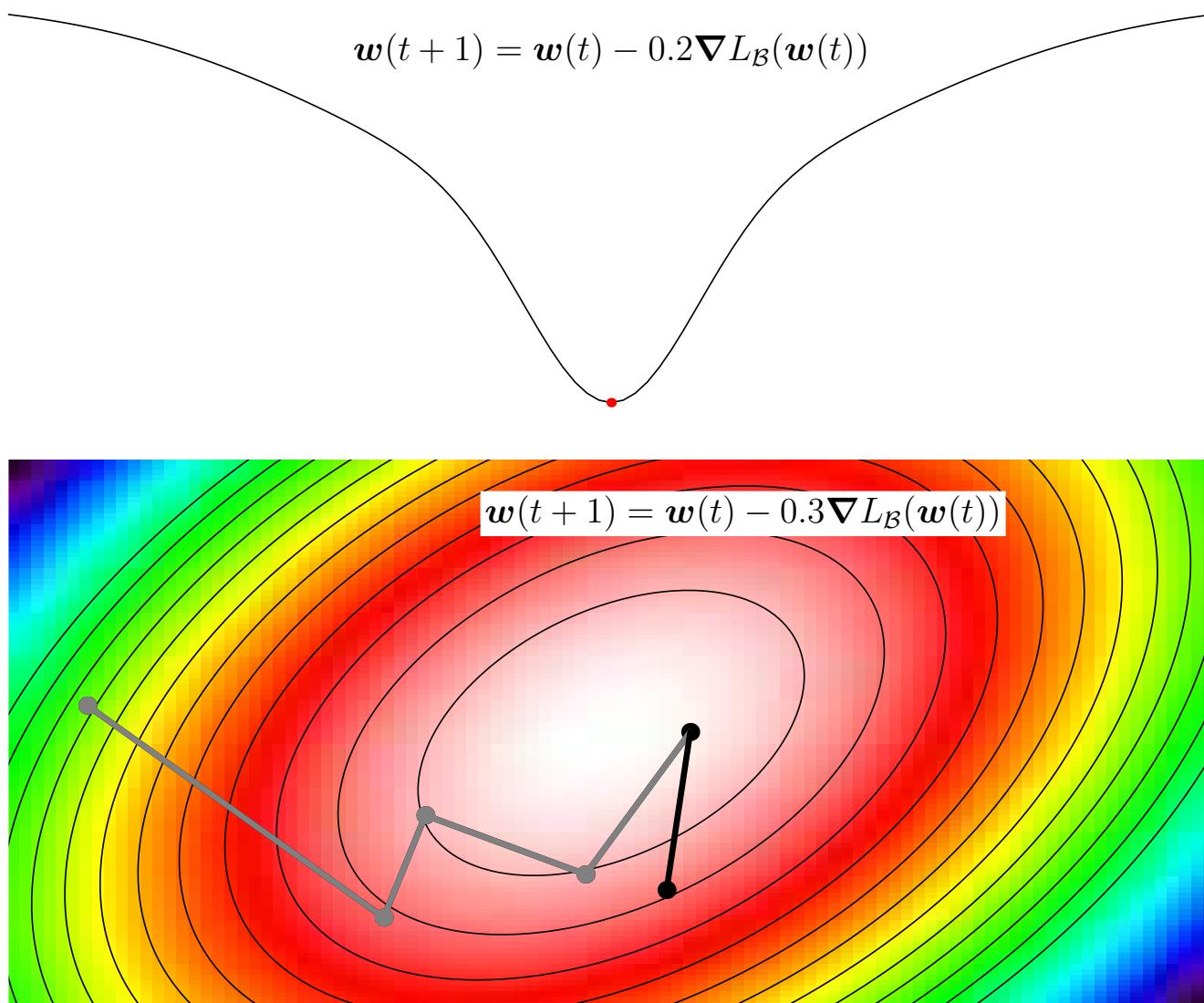
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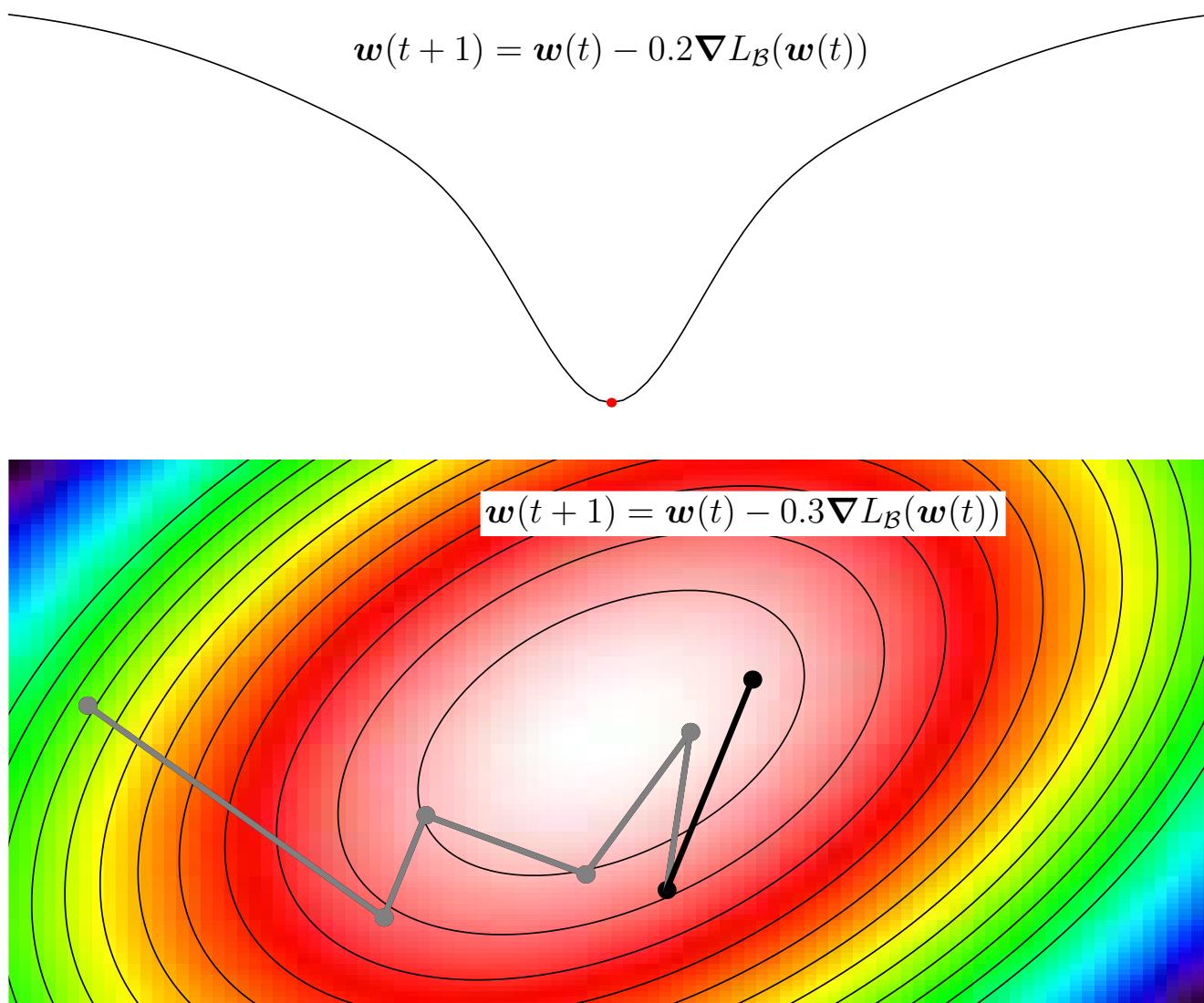
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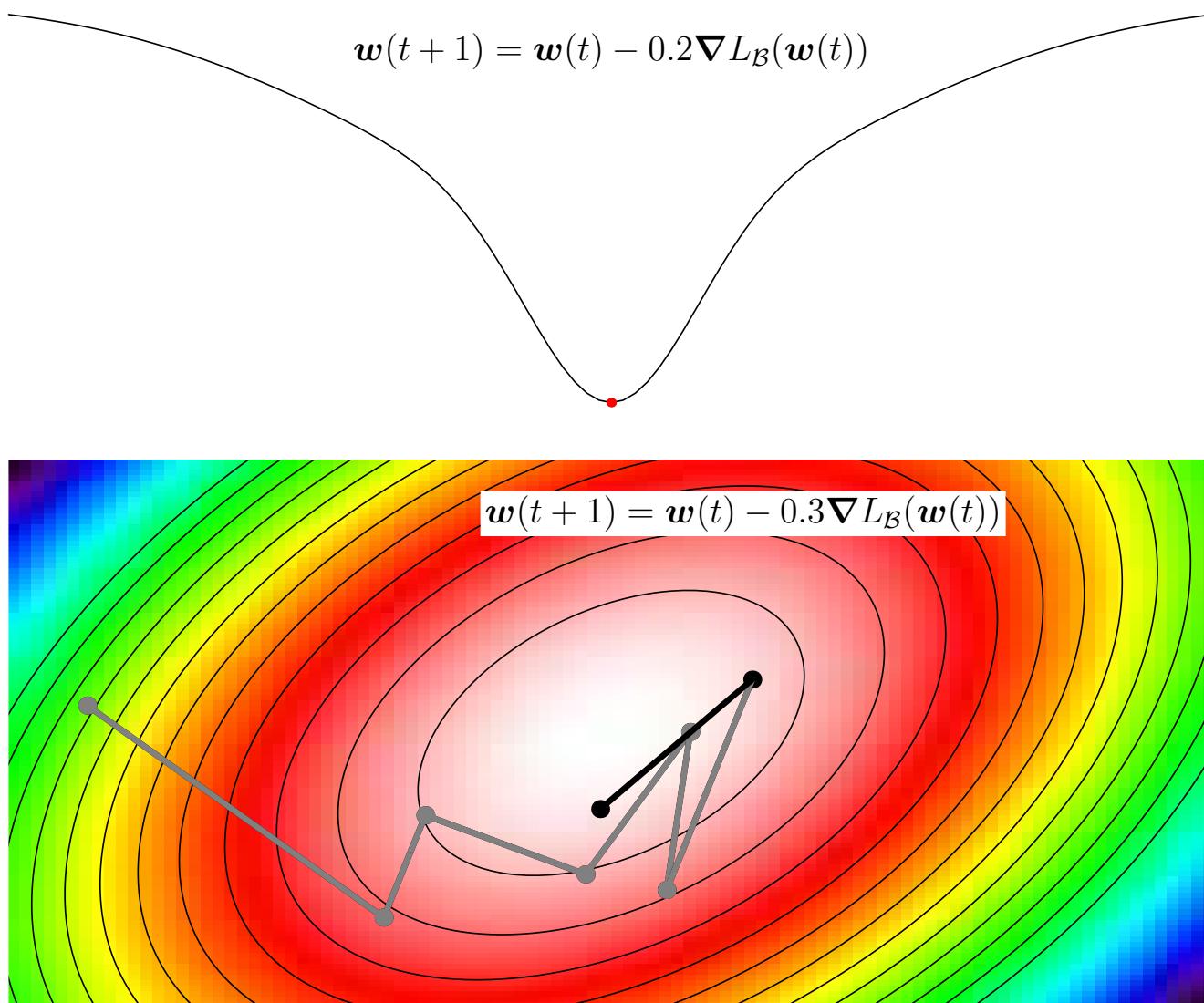
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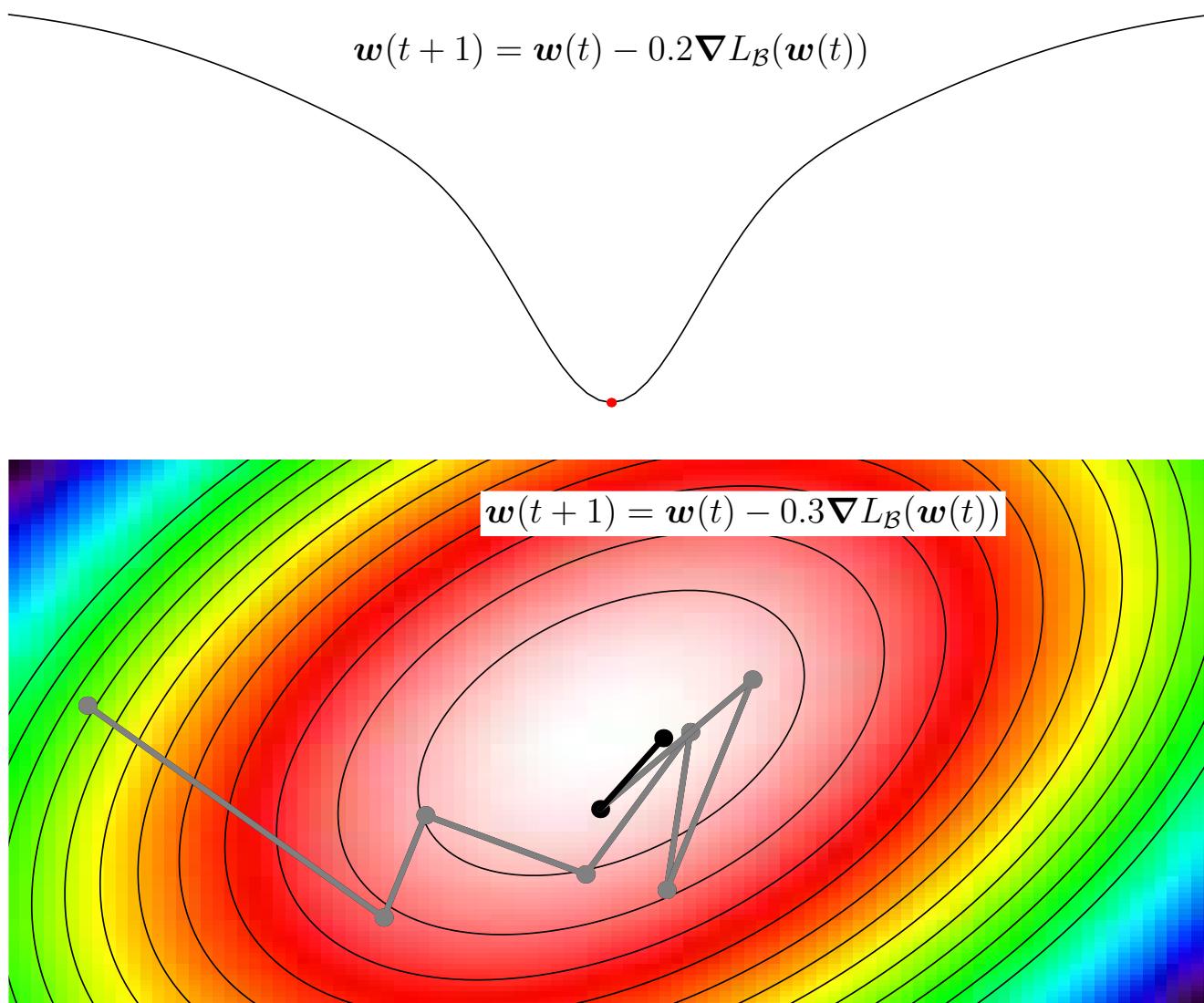
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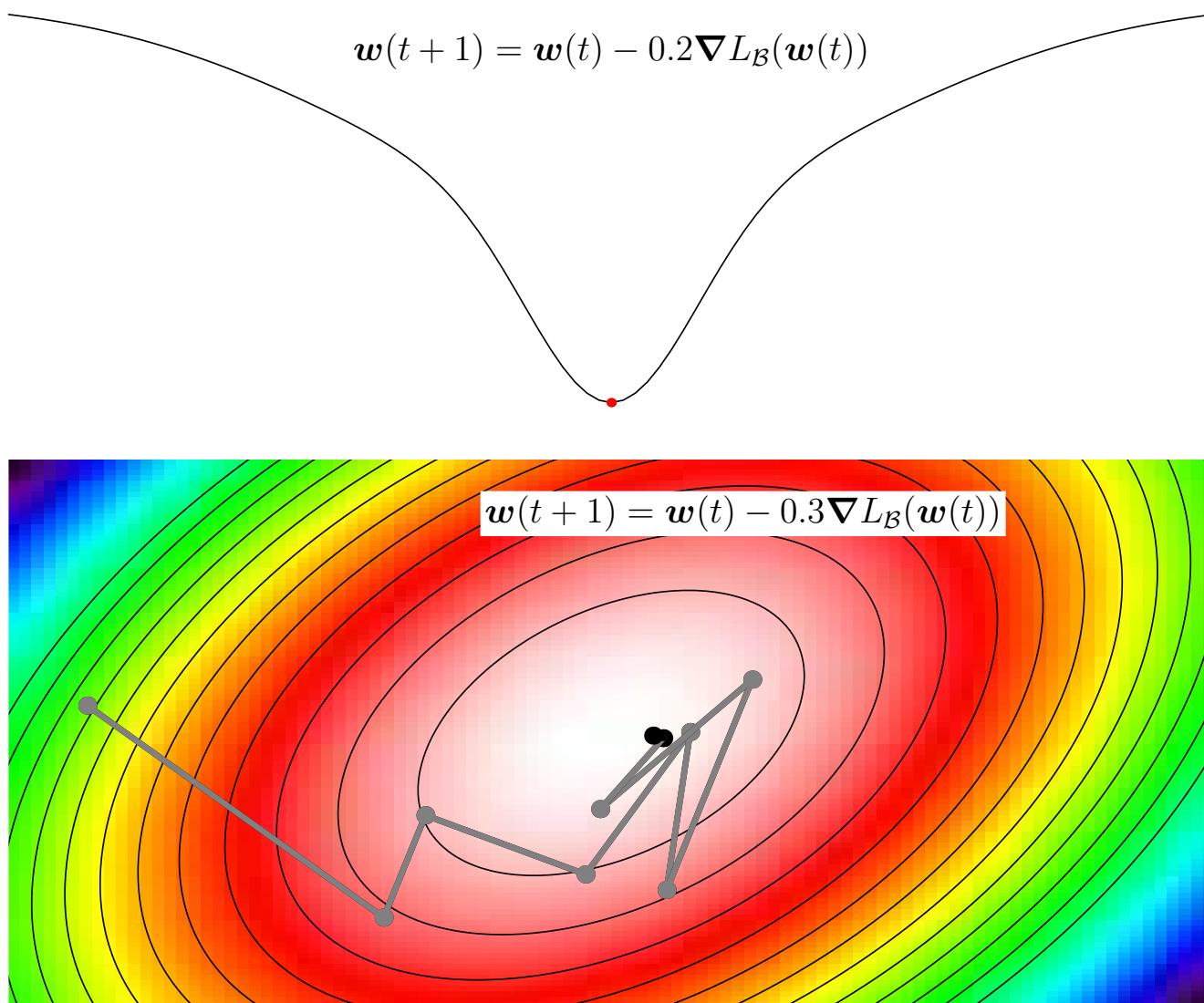
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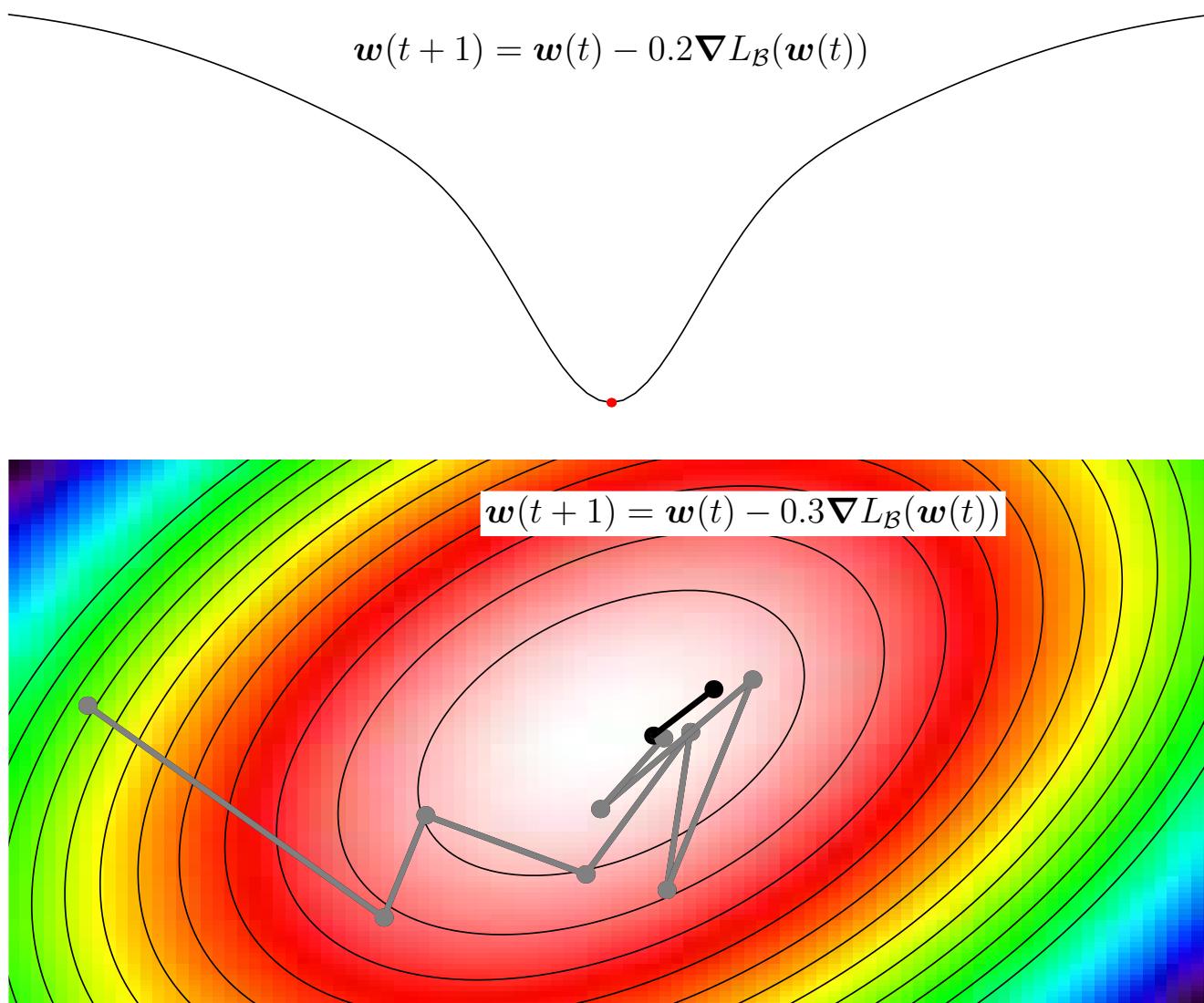
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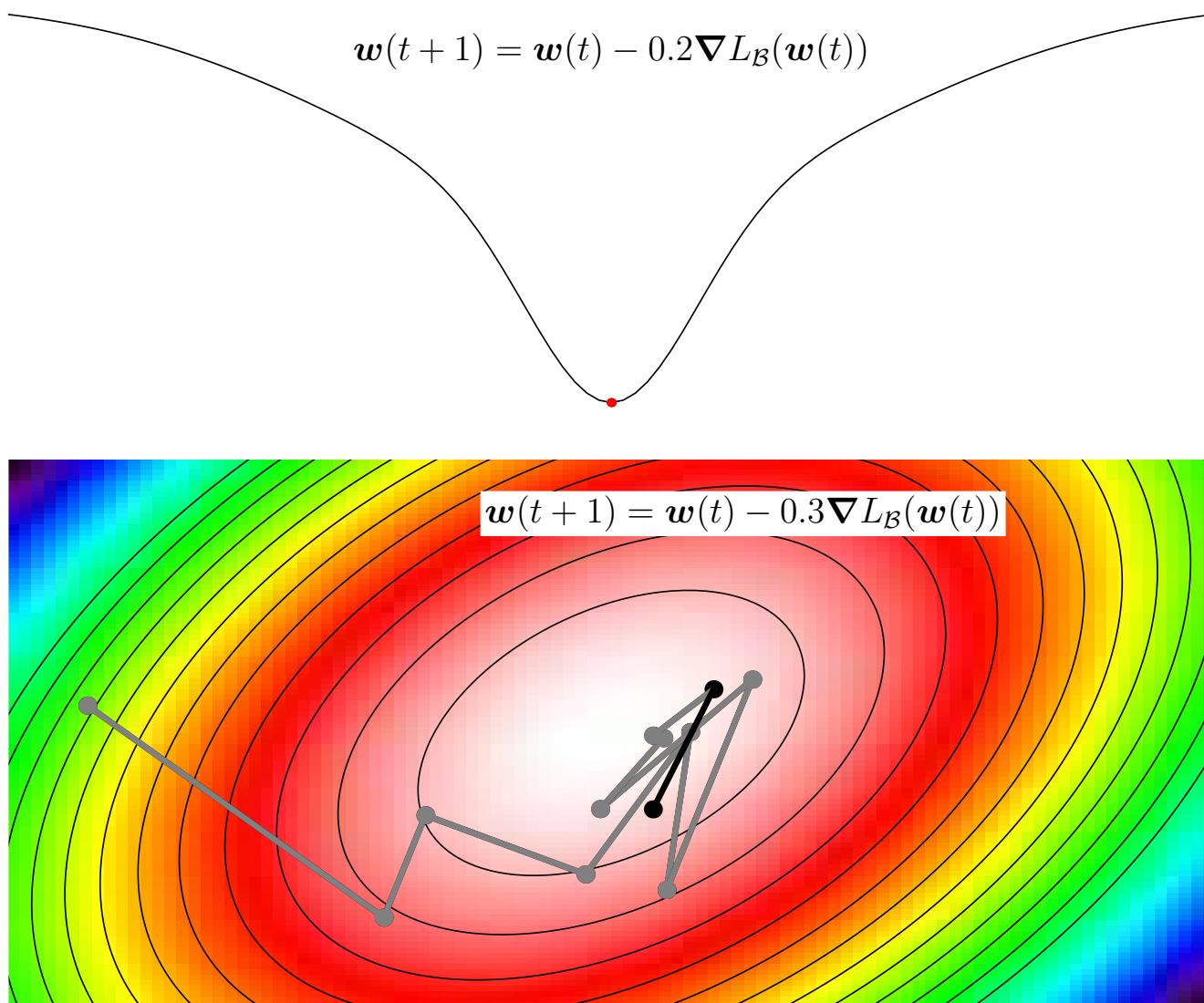
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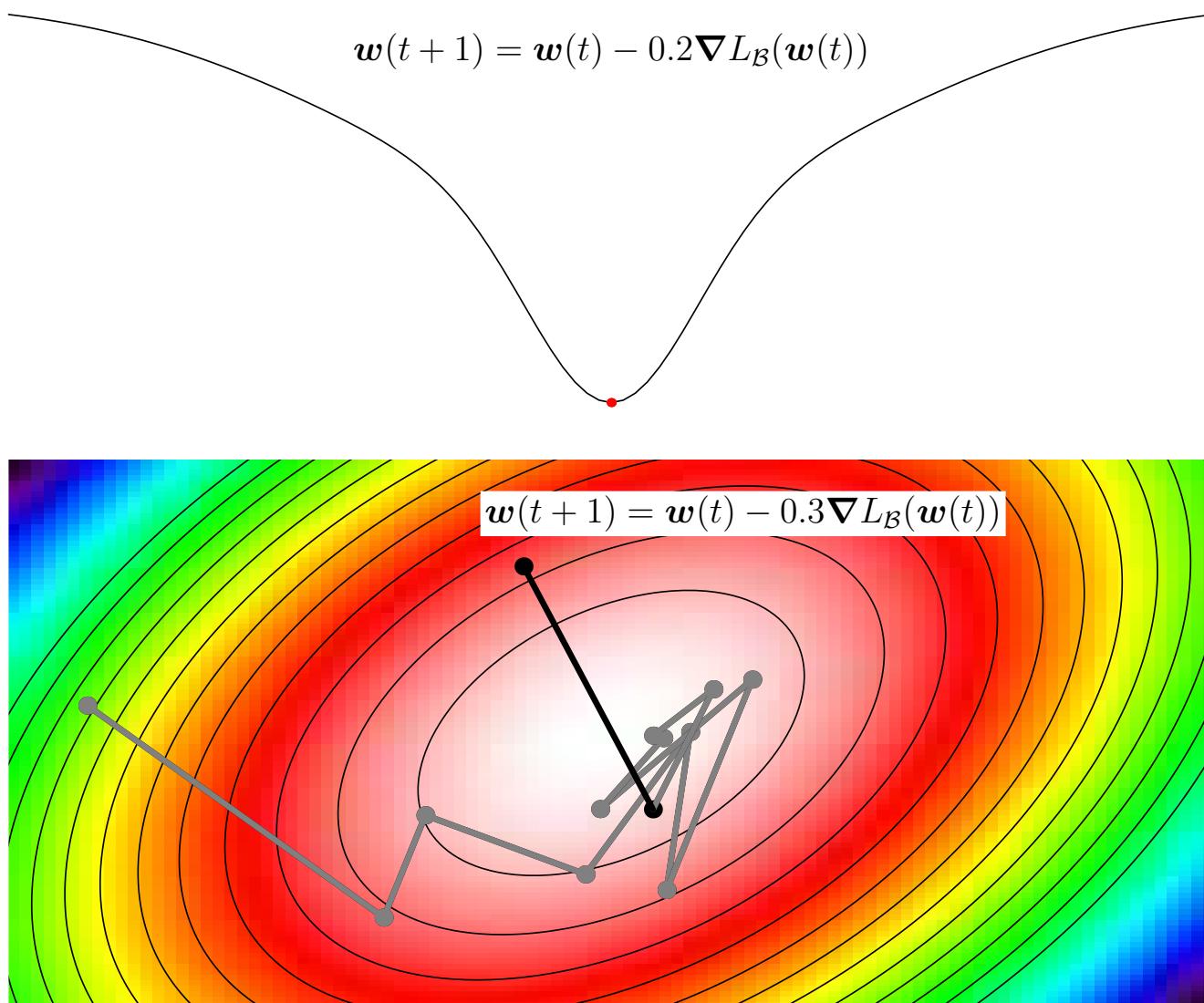
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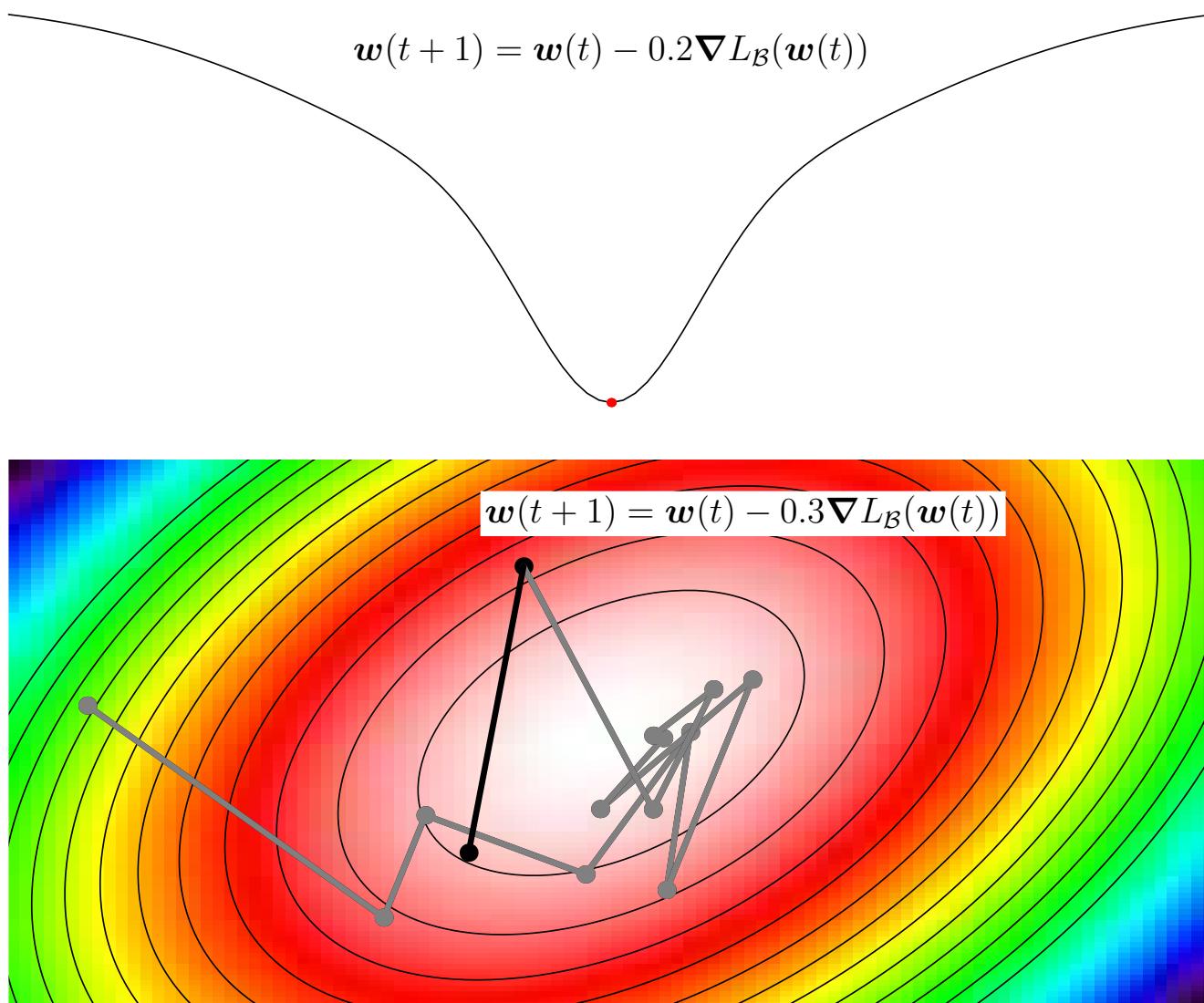
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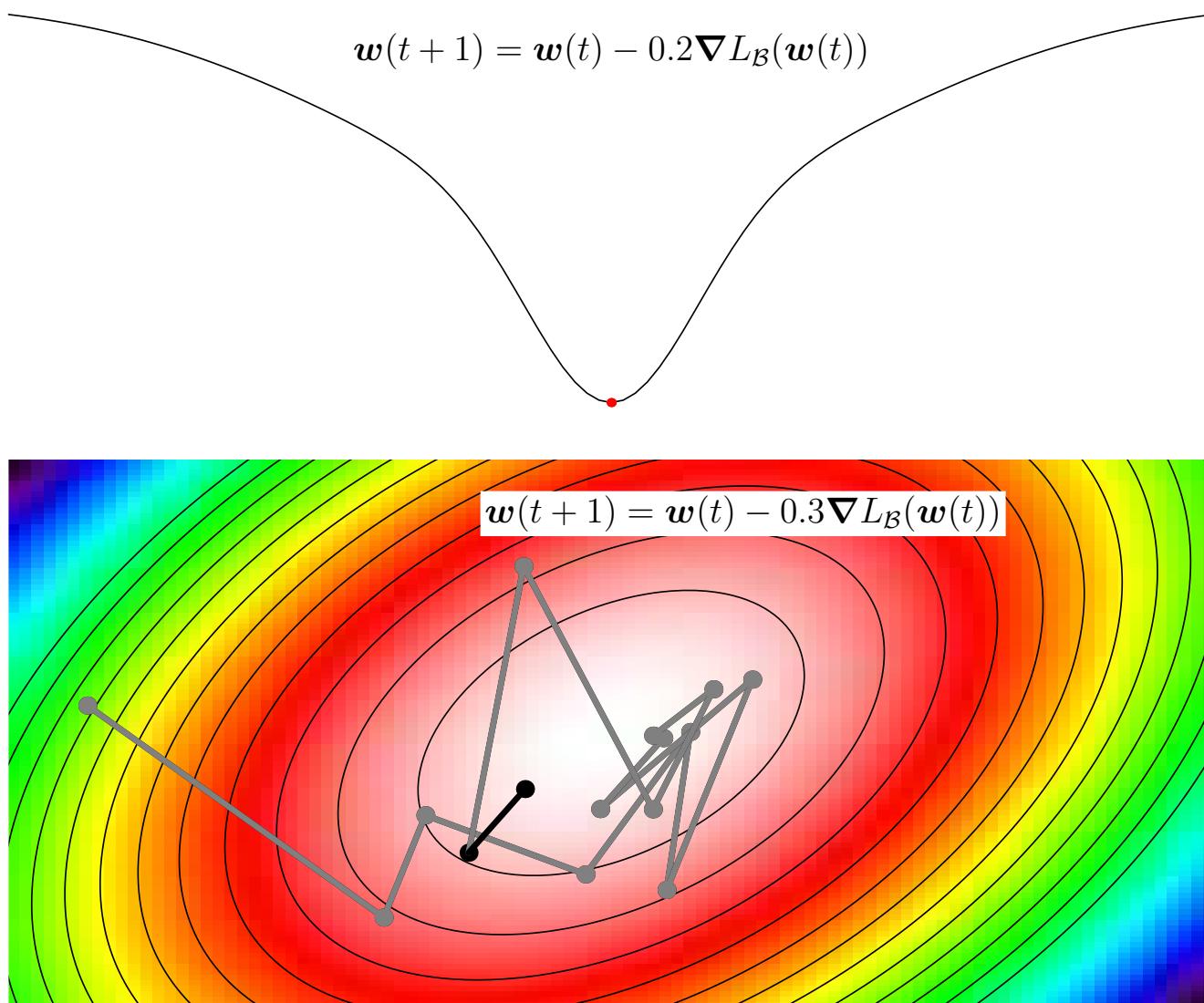
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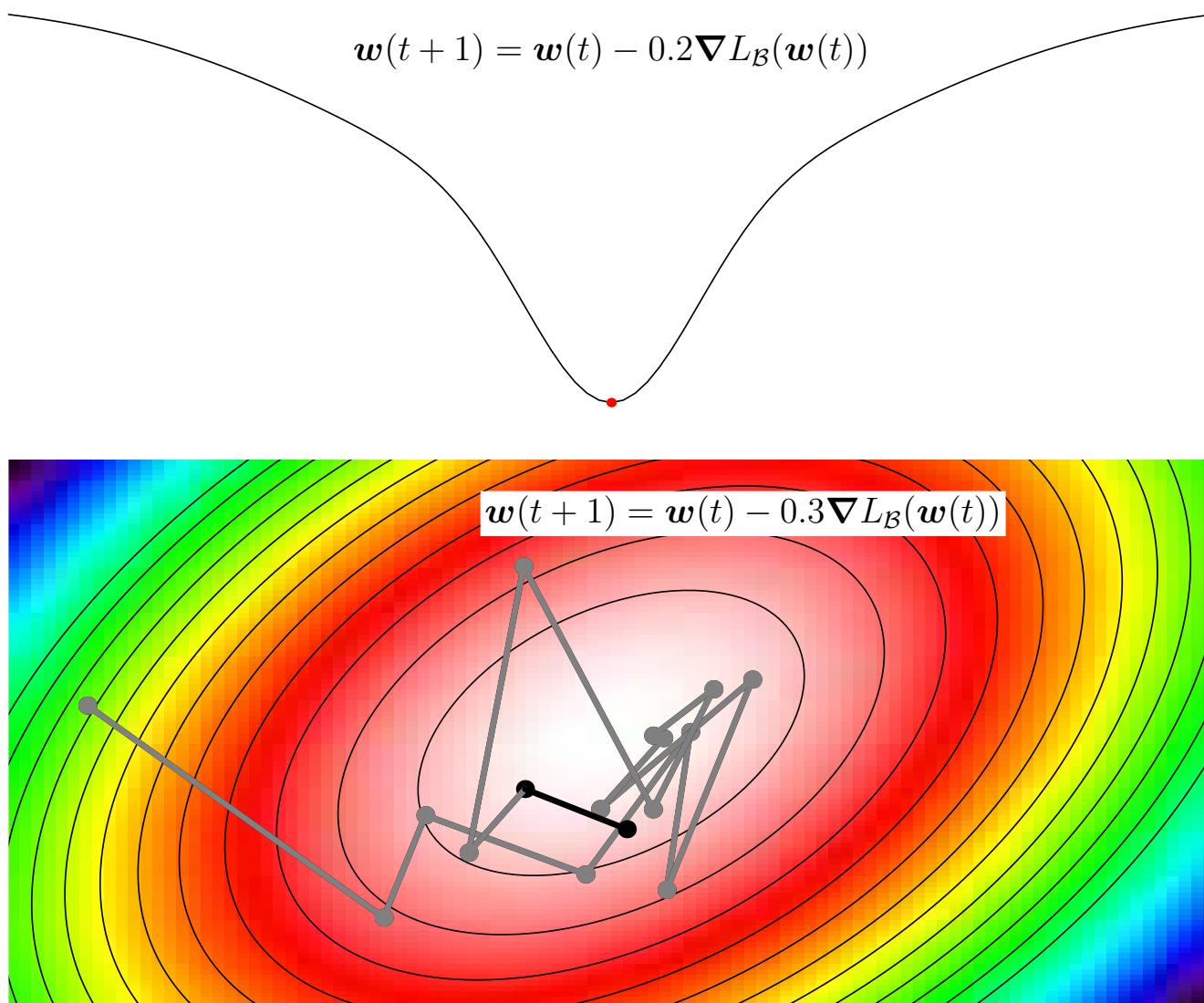
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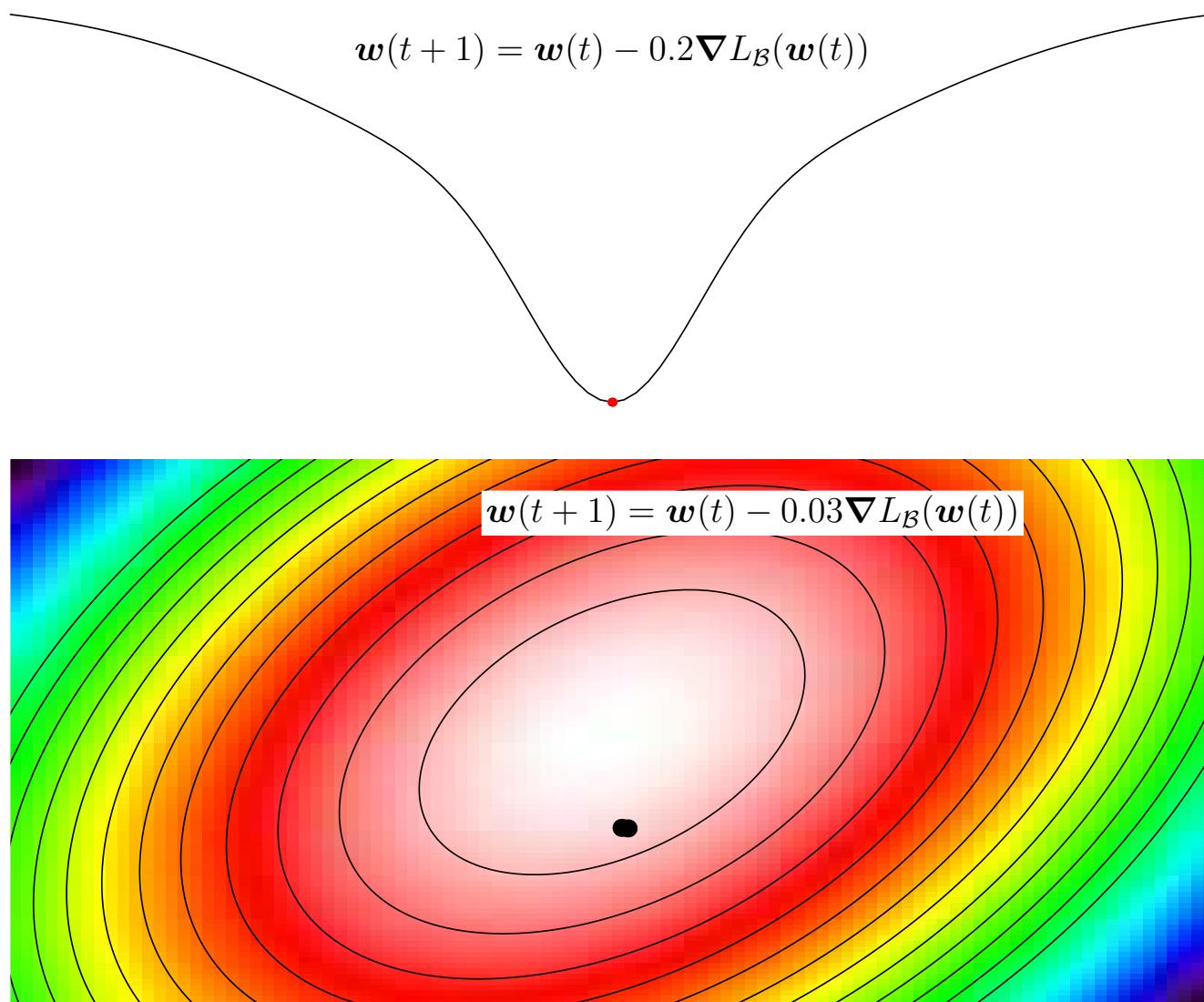
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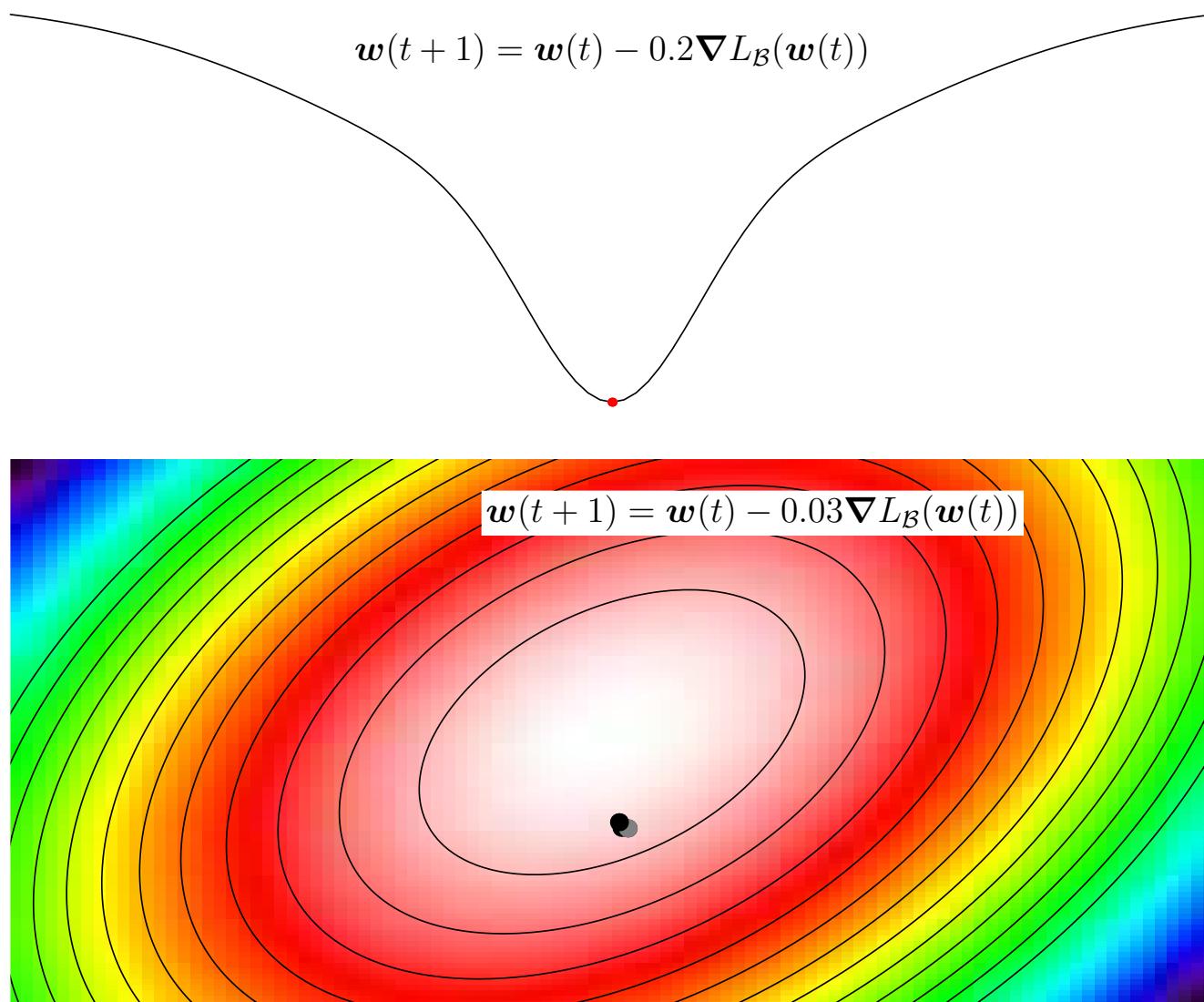
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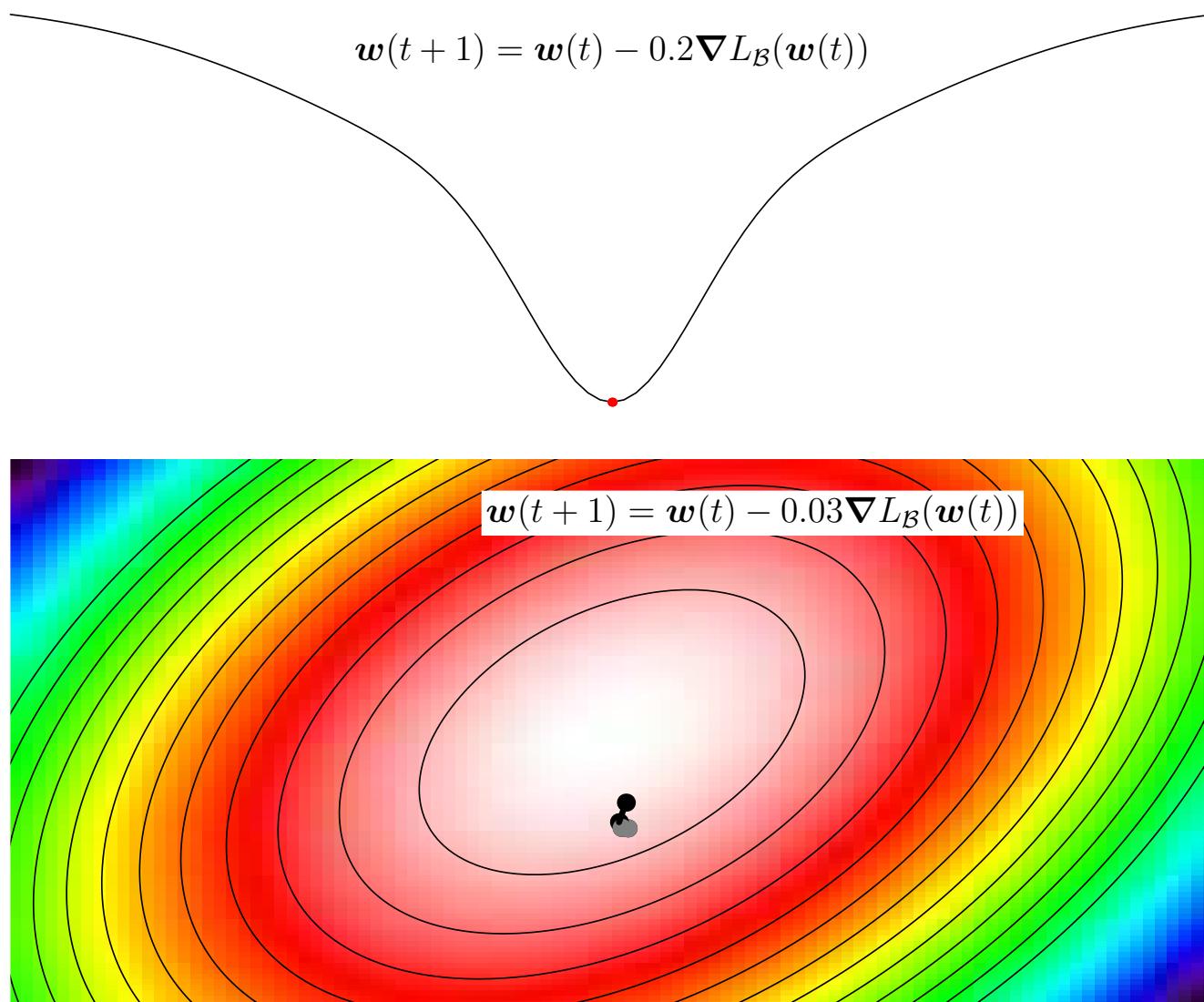
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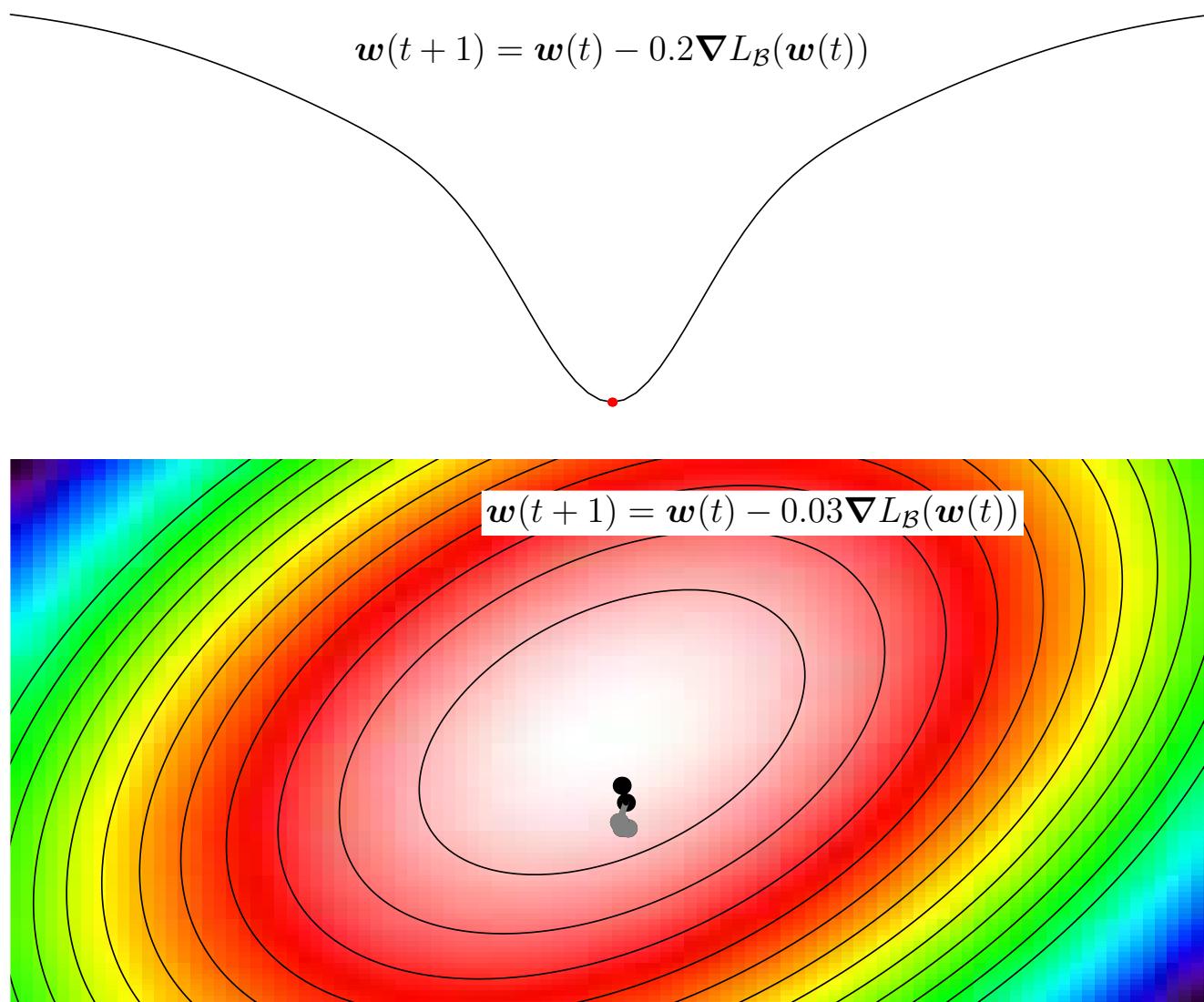
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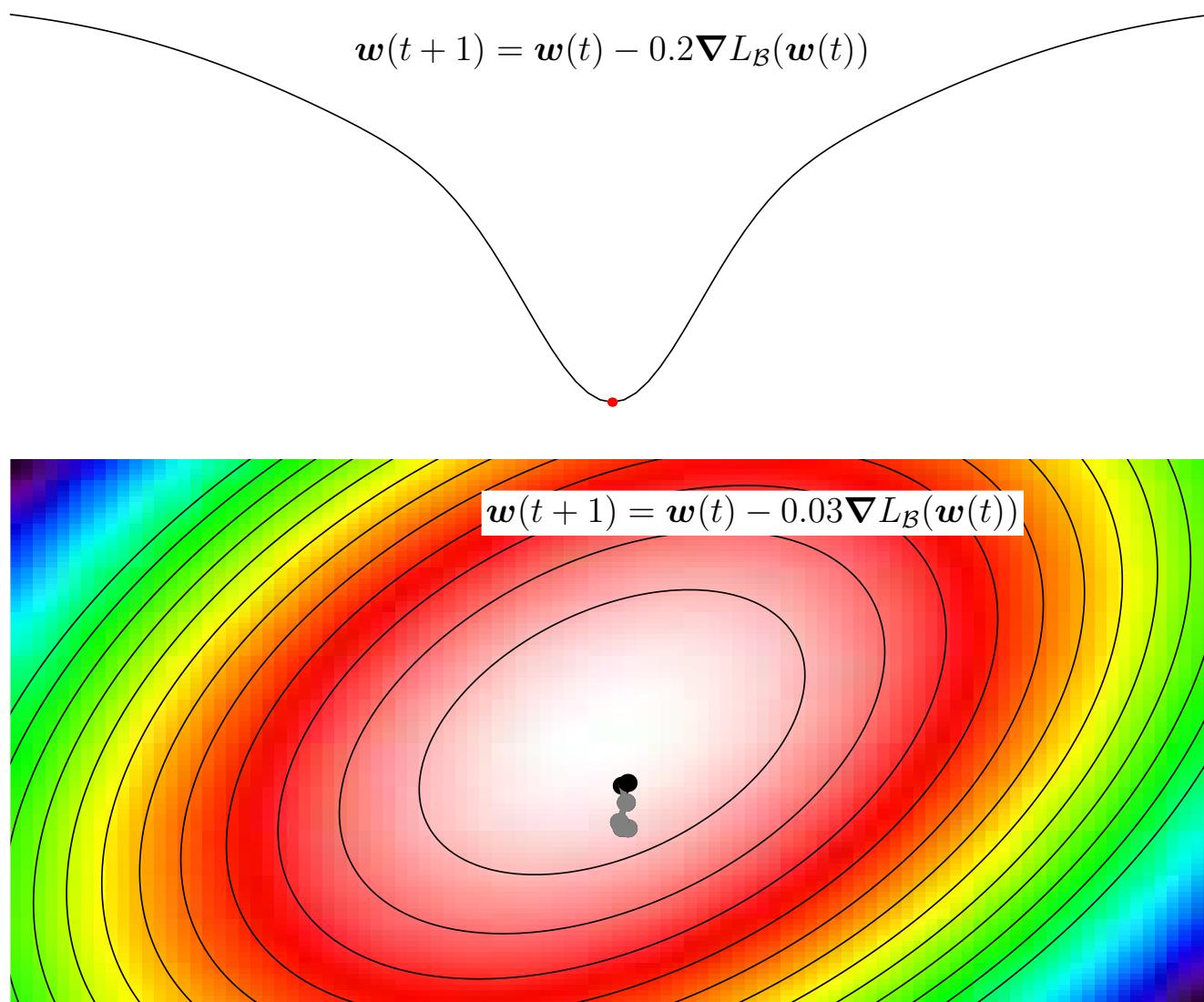
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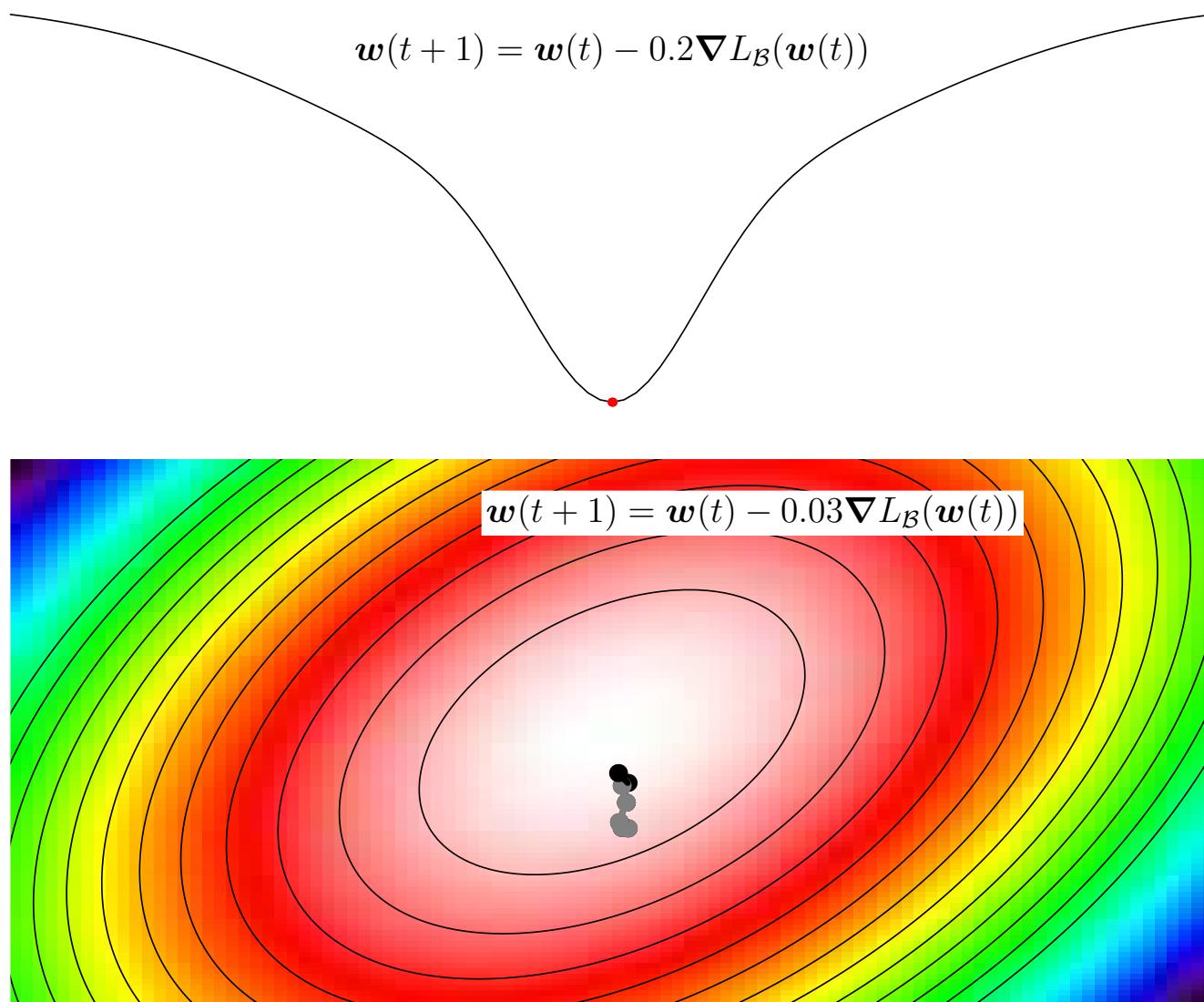
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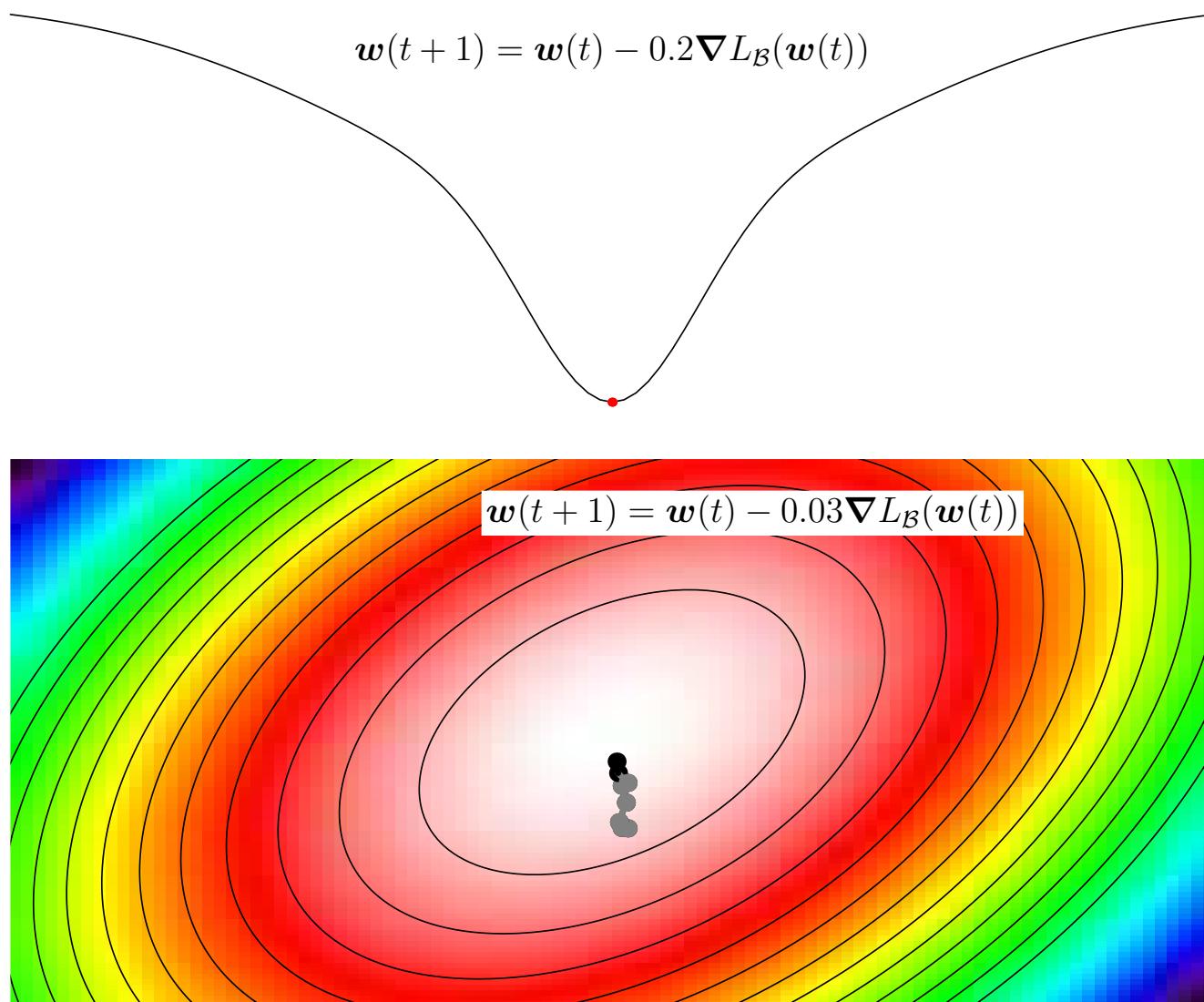
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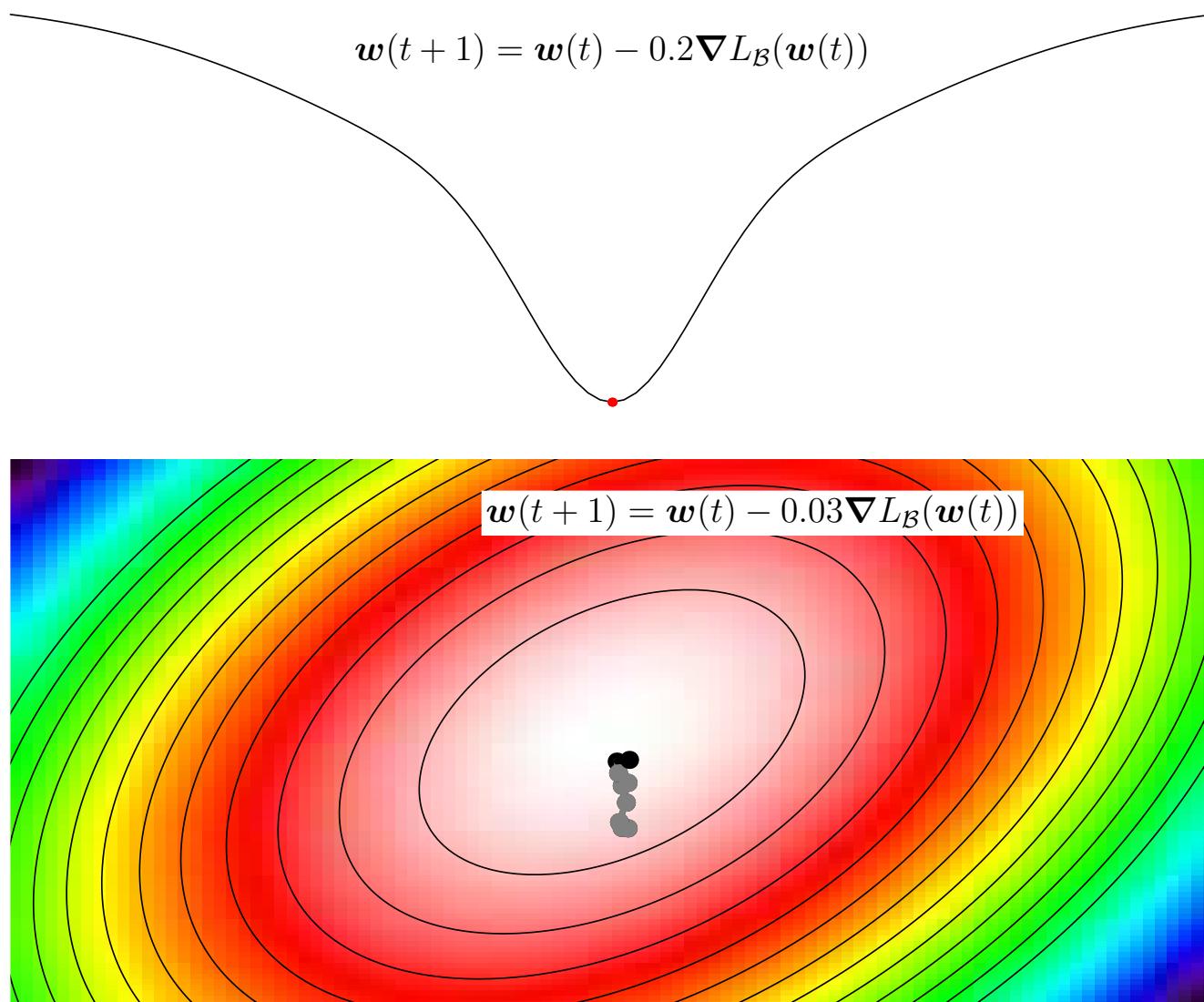
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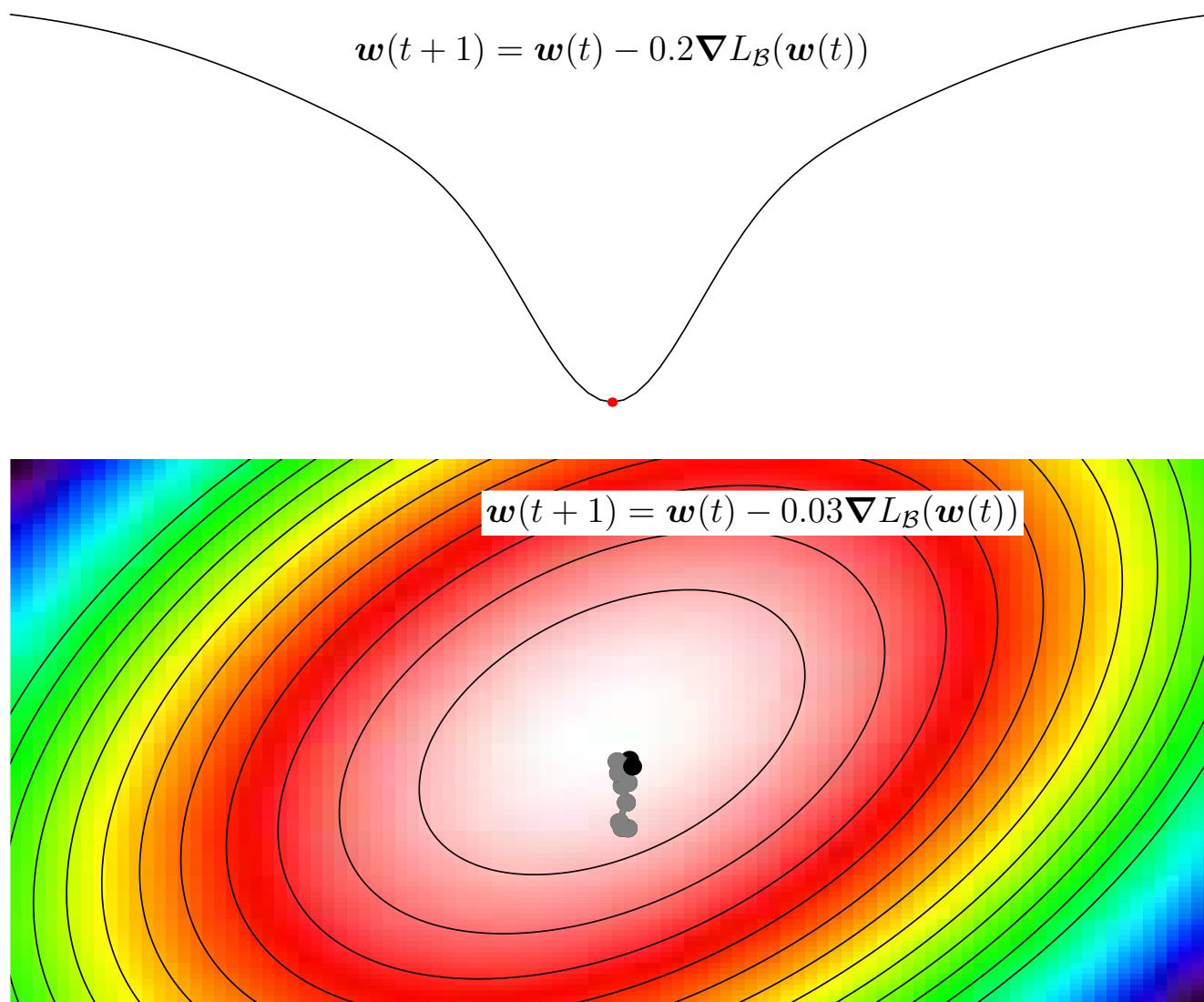
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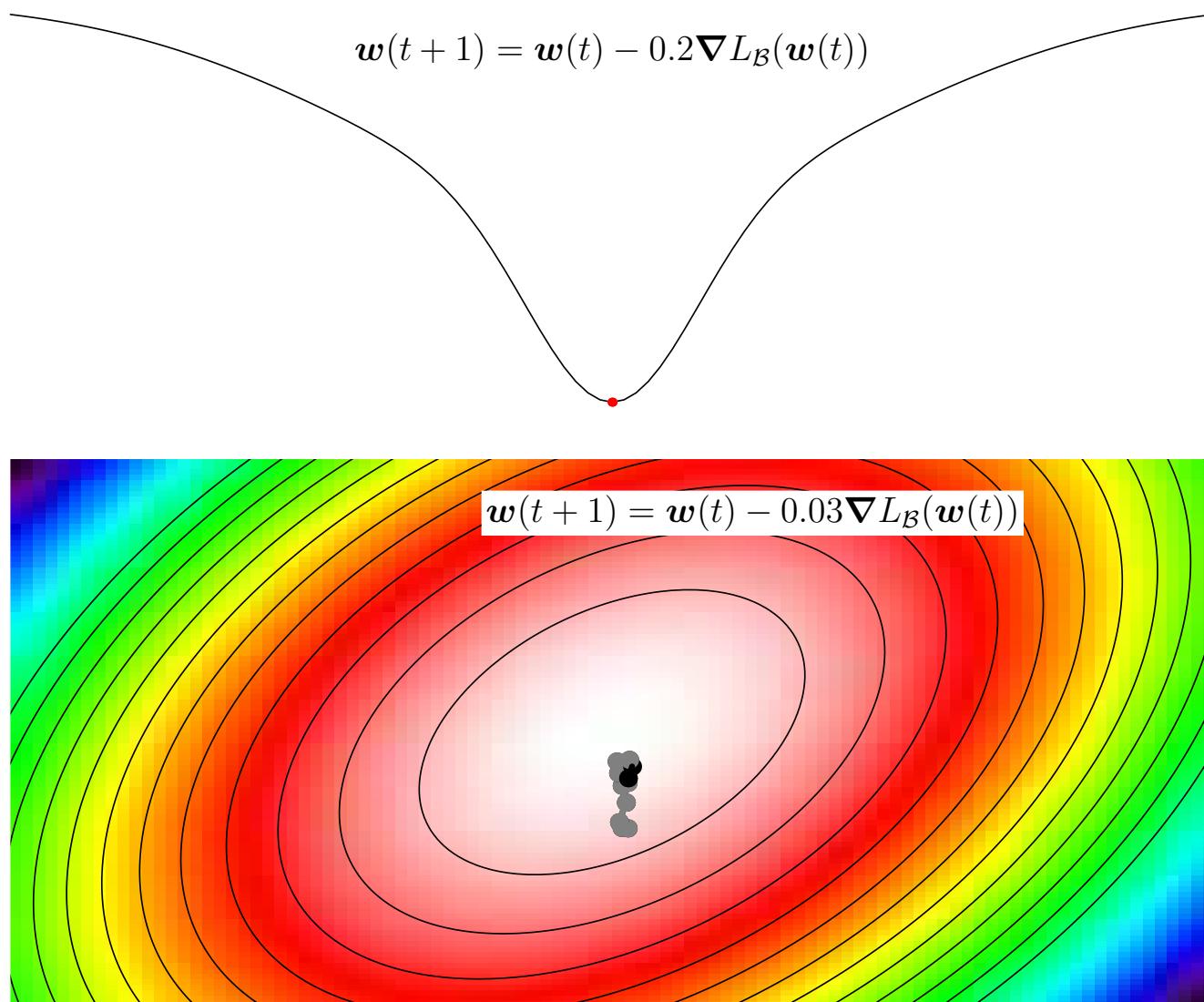
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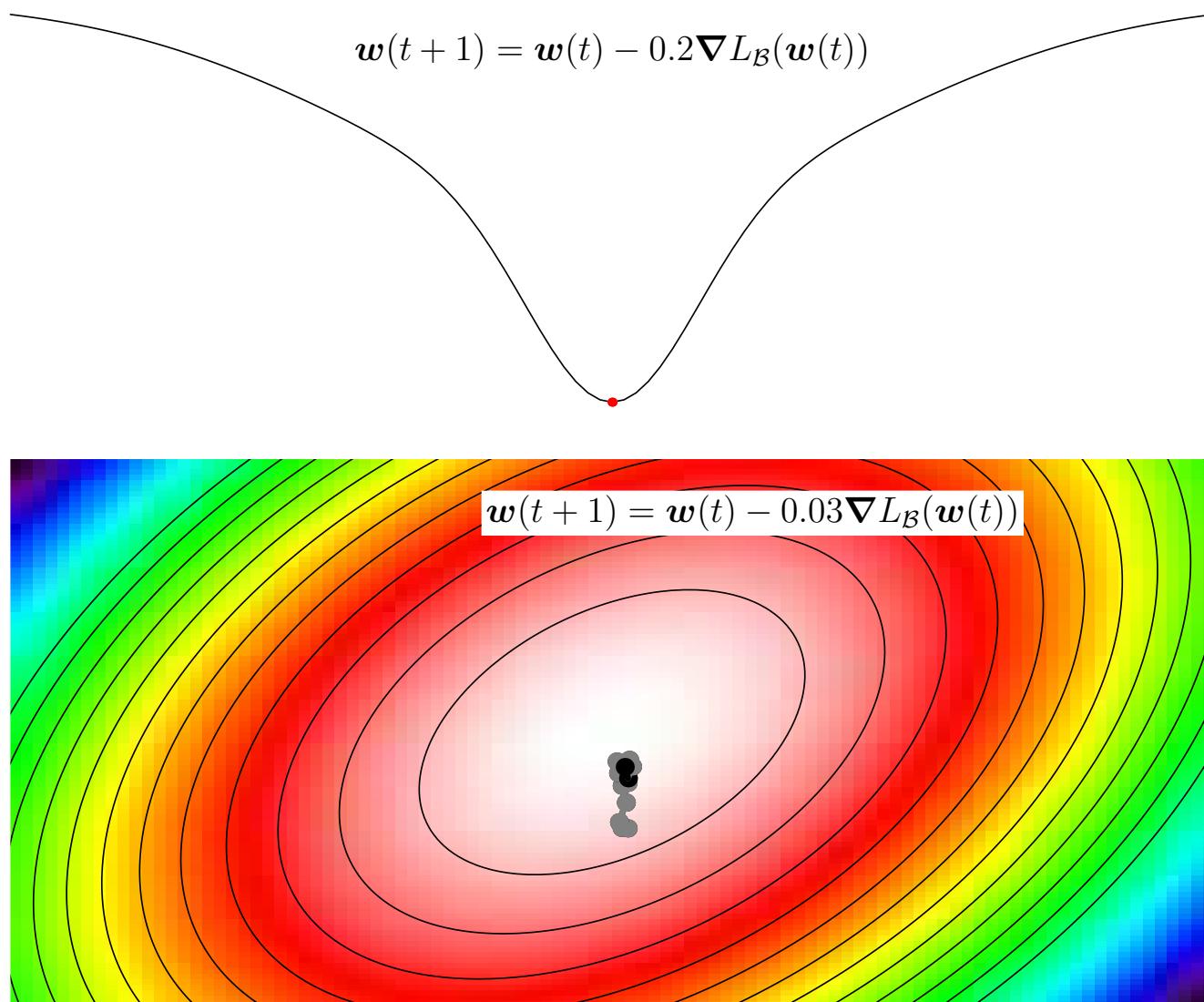
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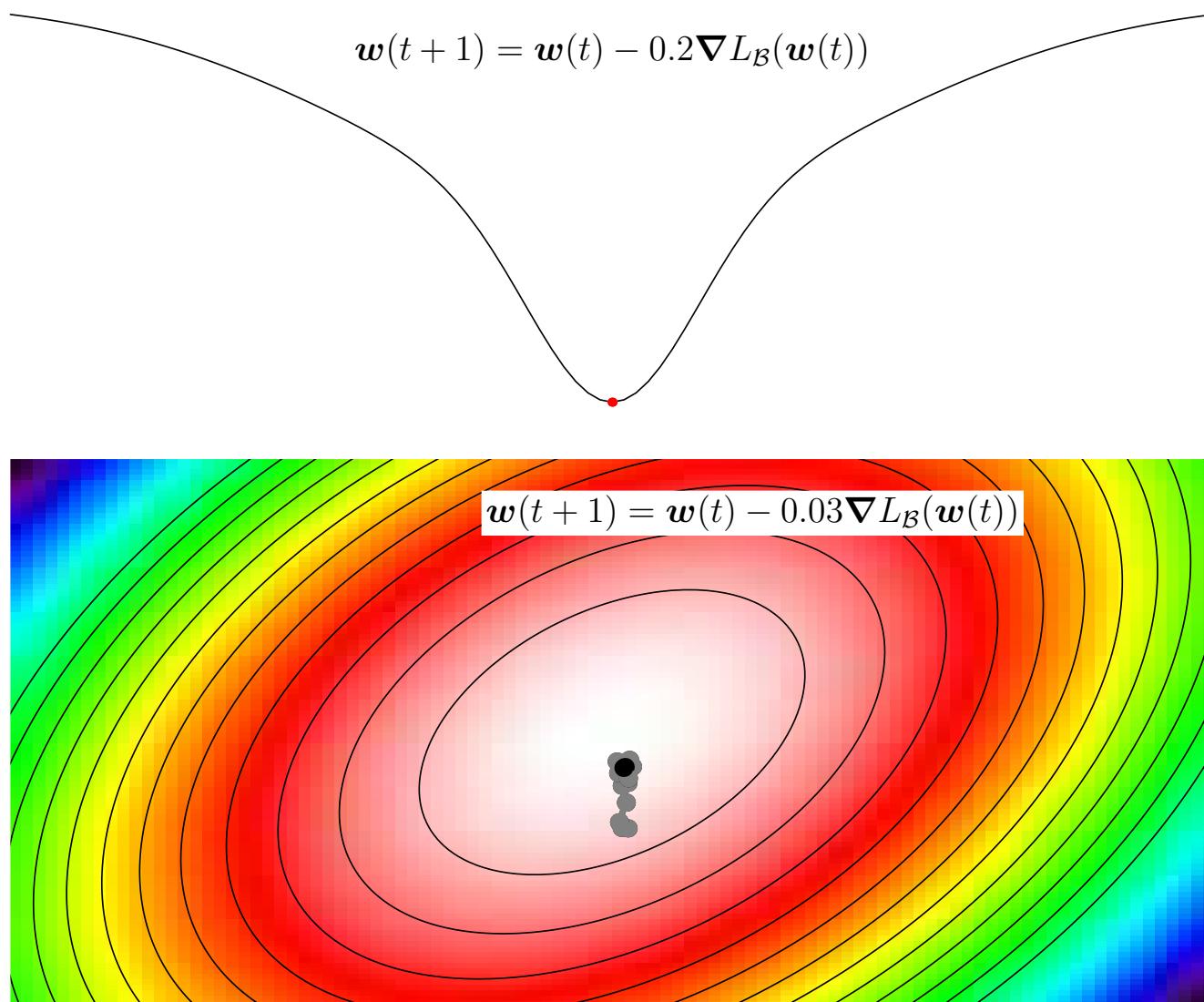
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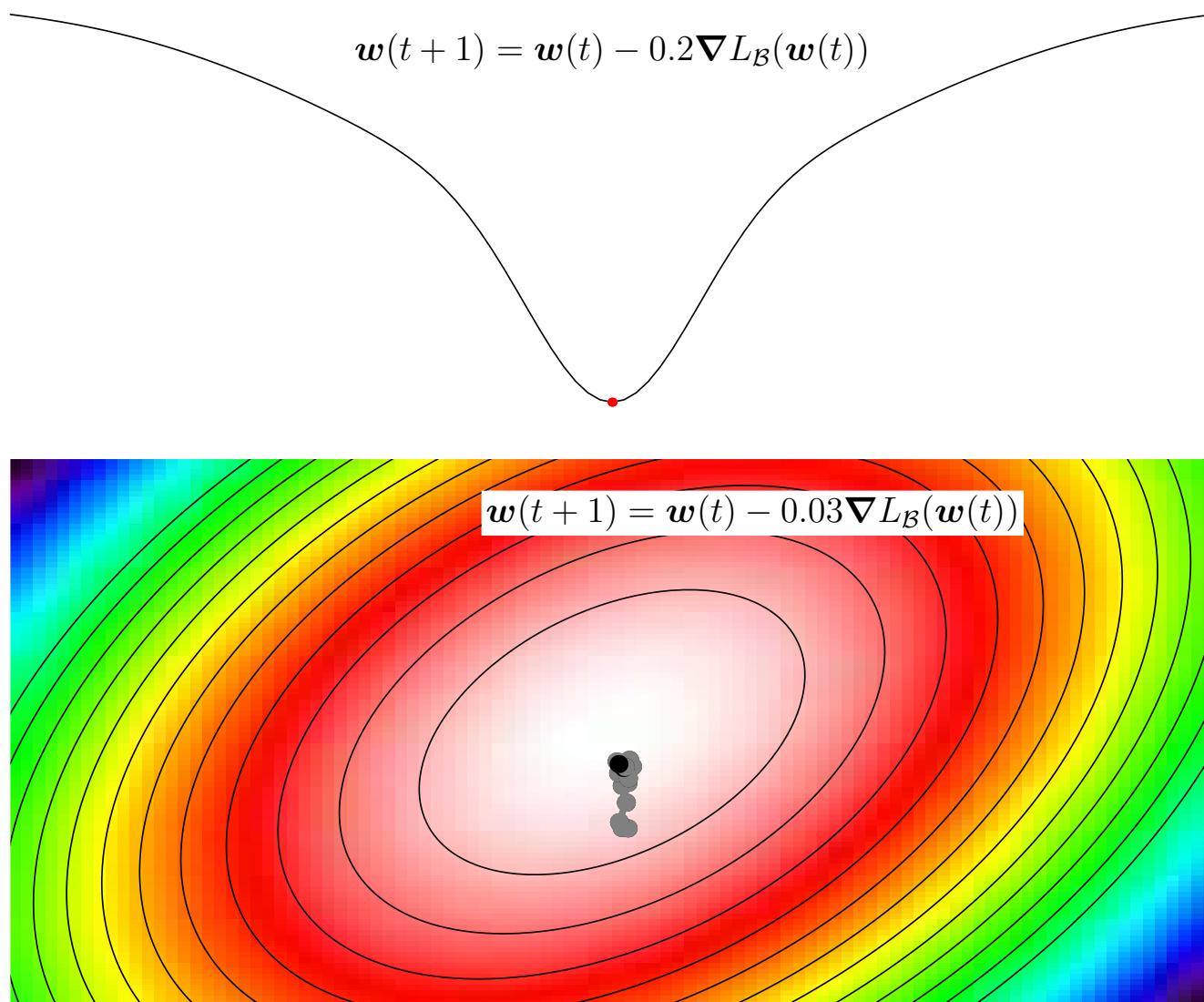
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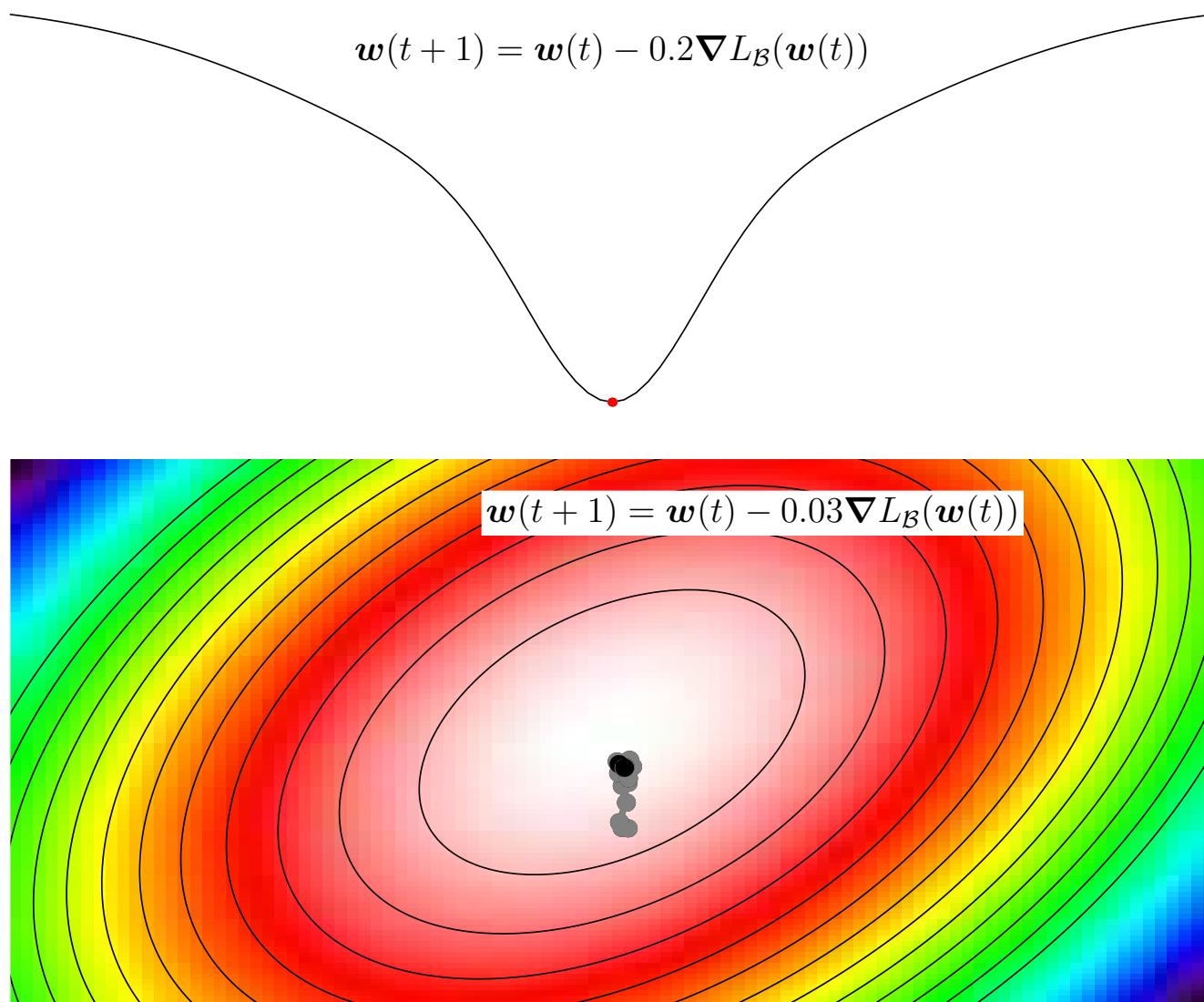
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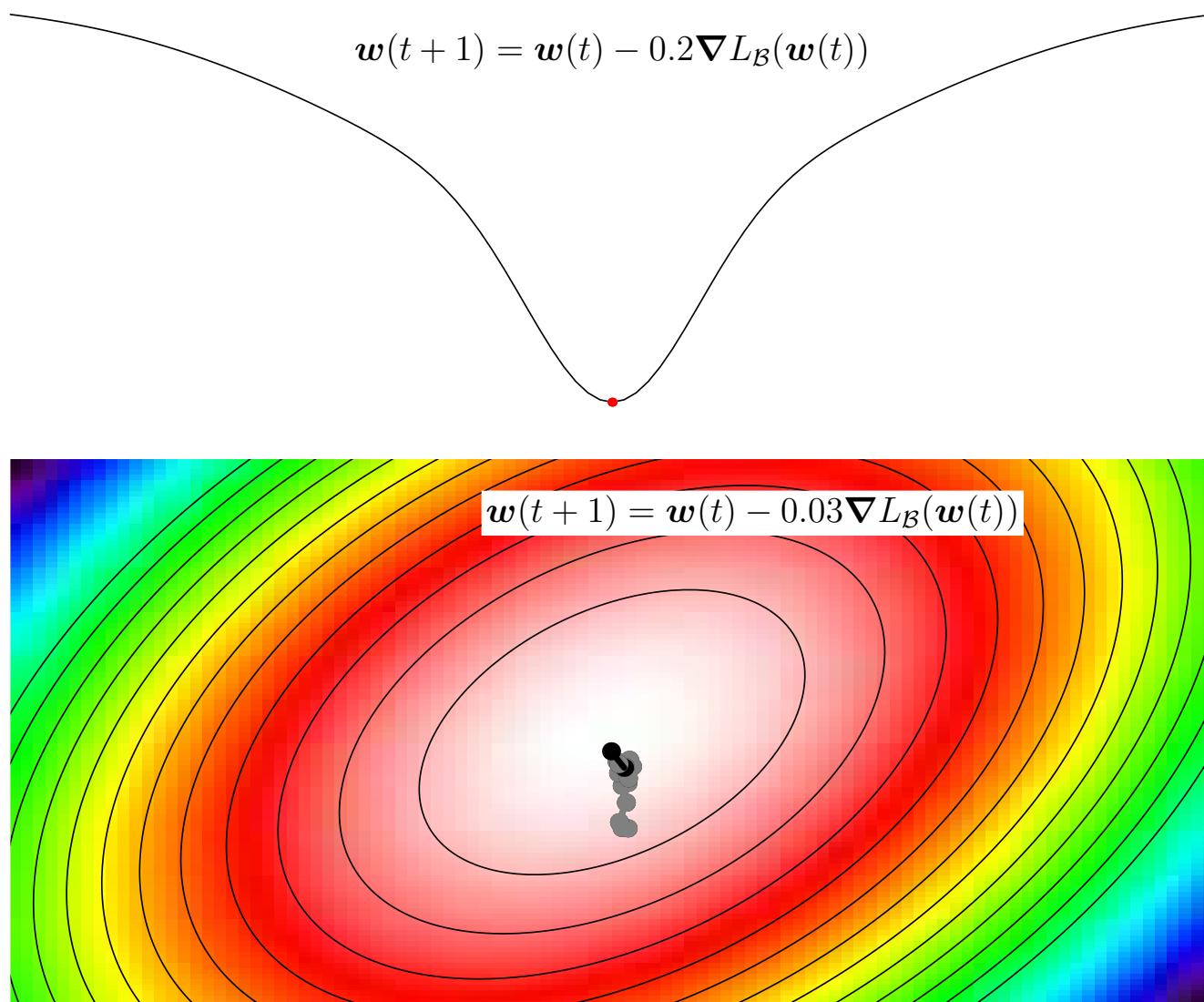
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# Symmetries

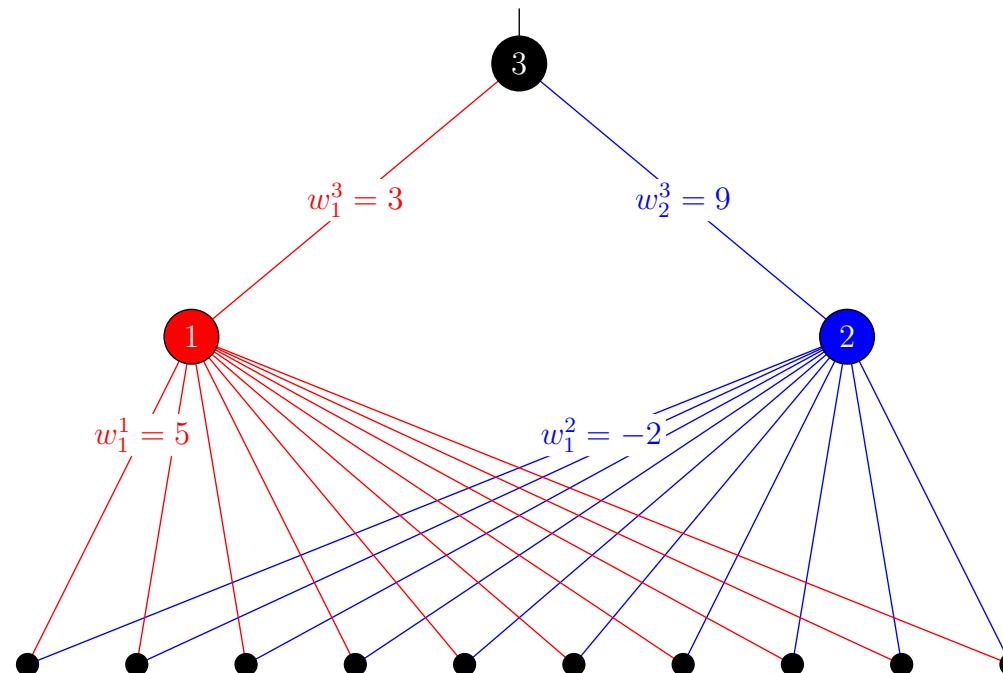
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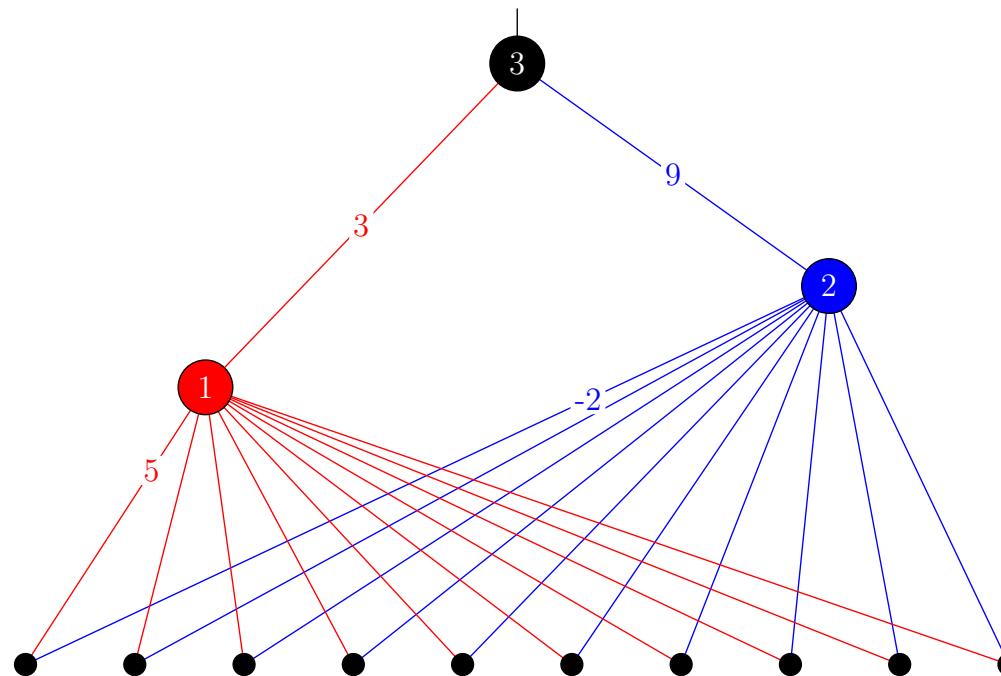
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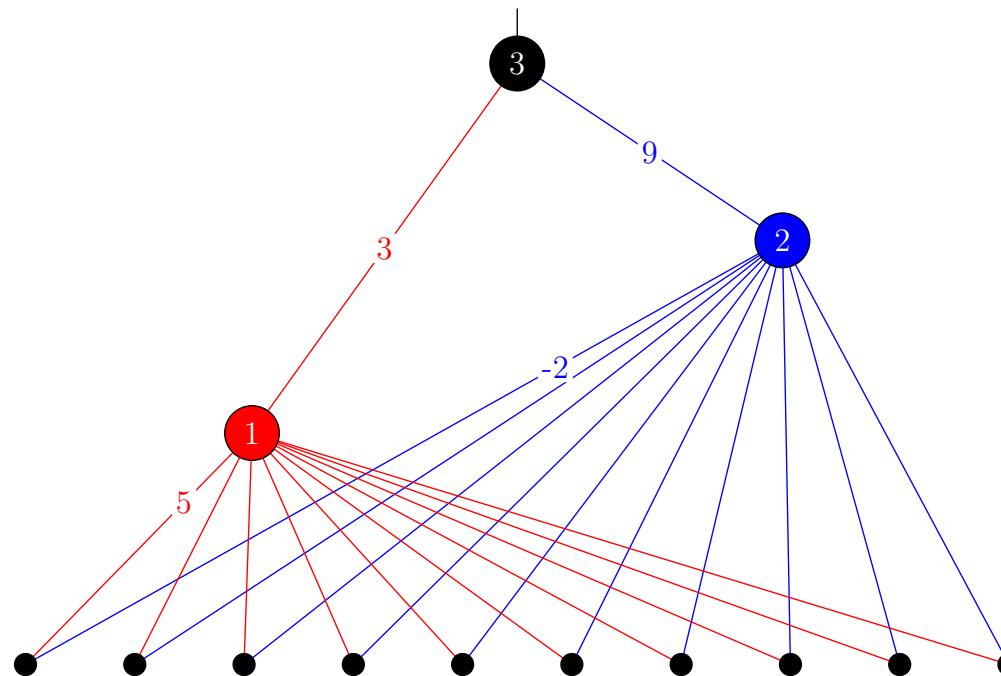
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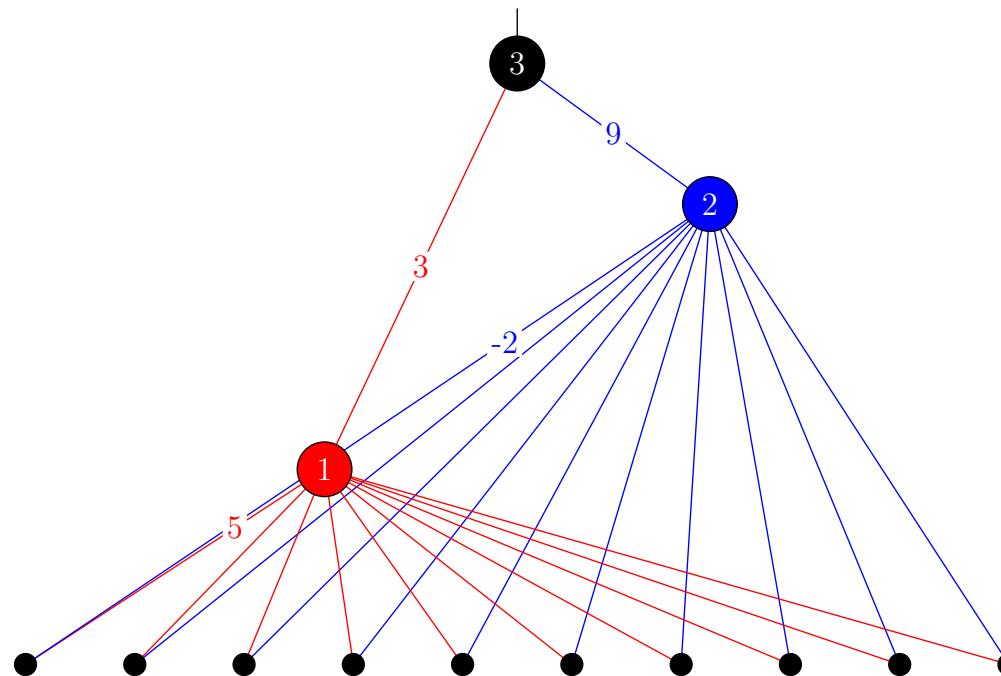
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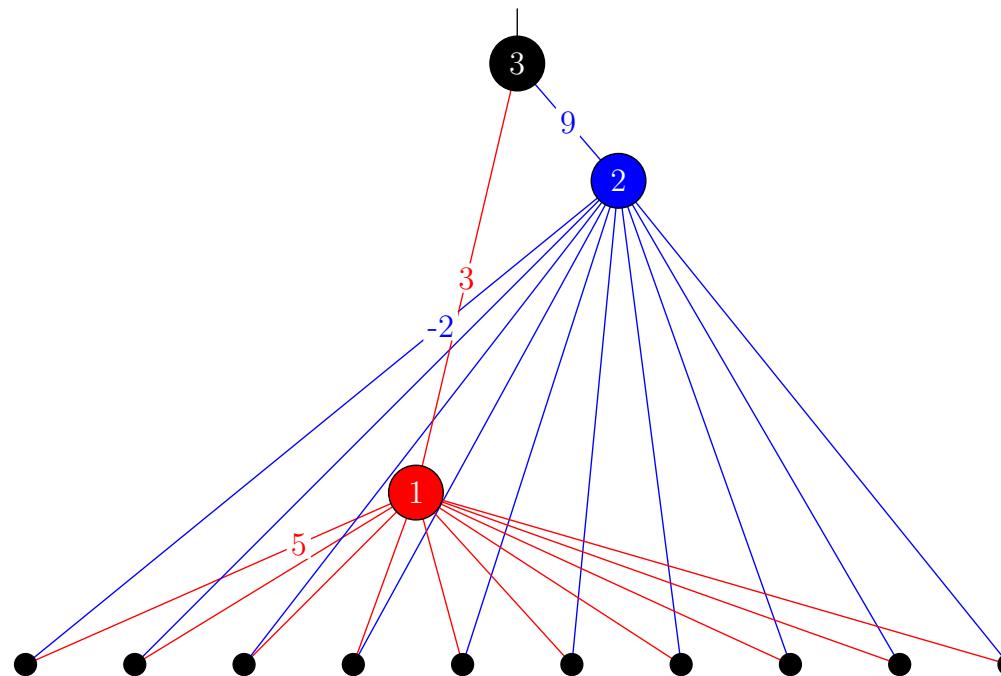
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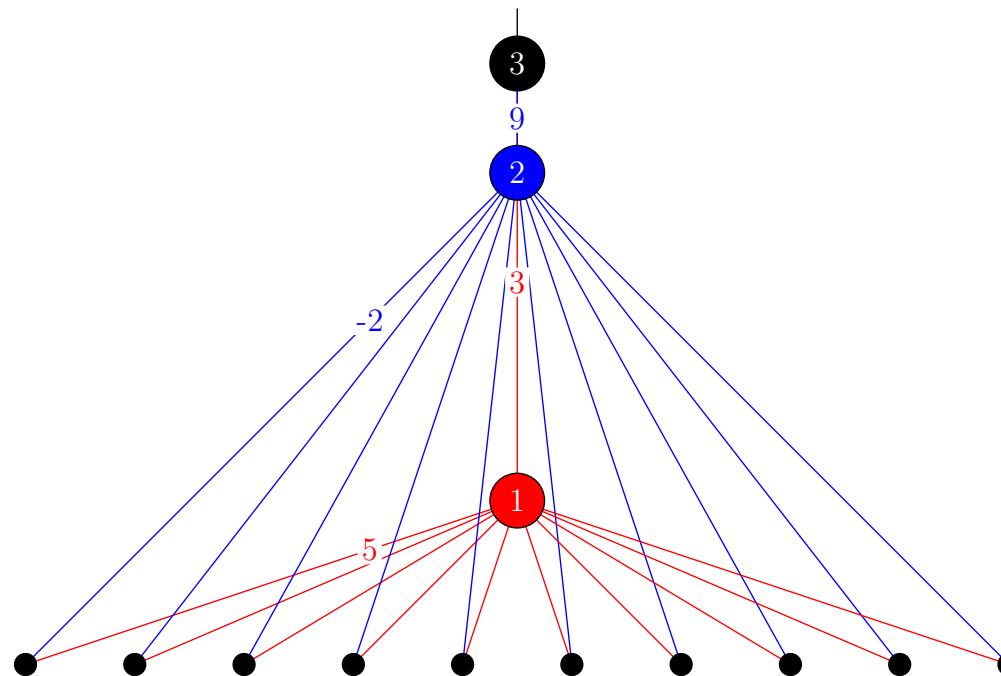
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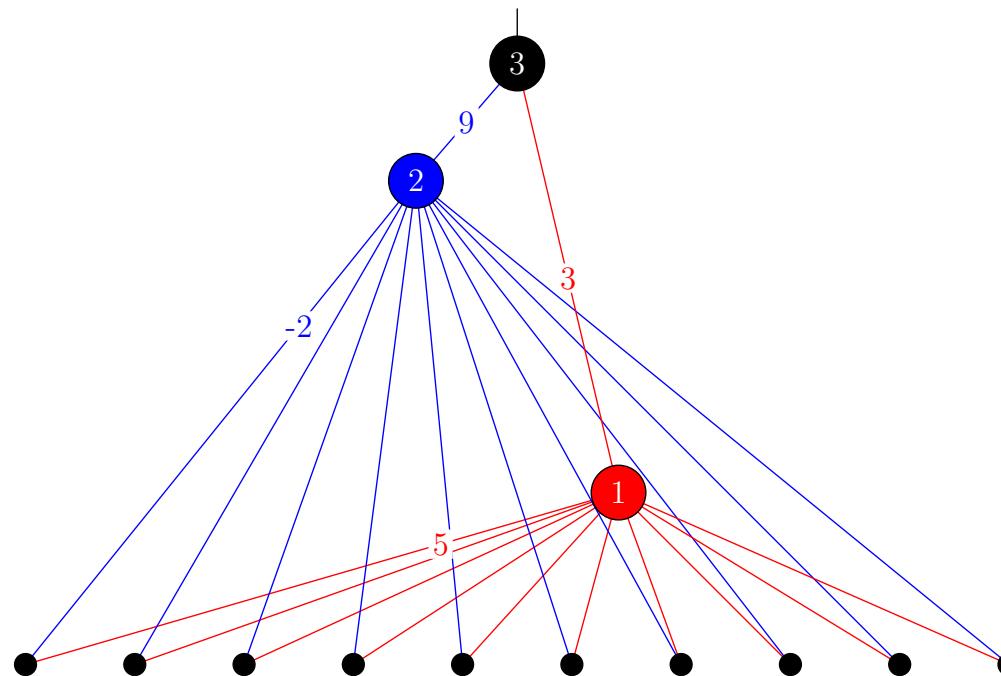
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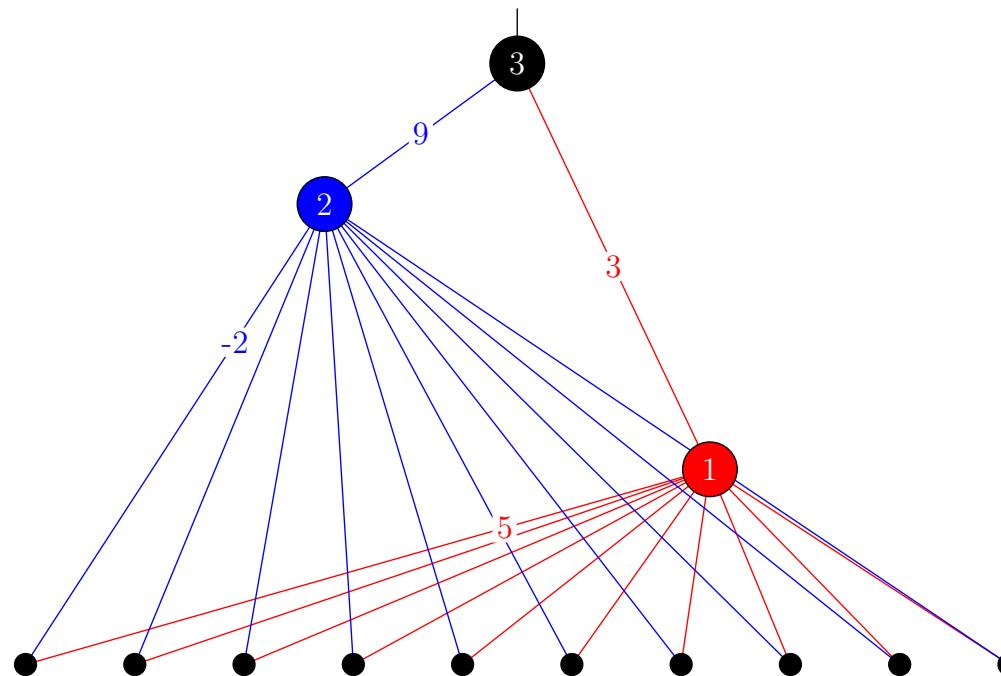
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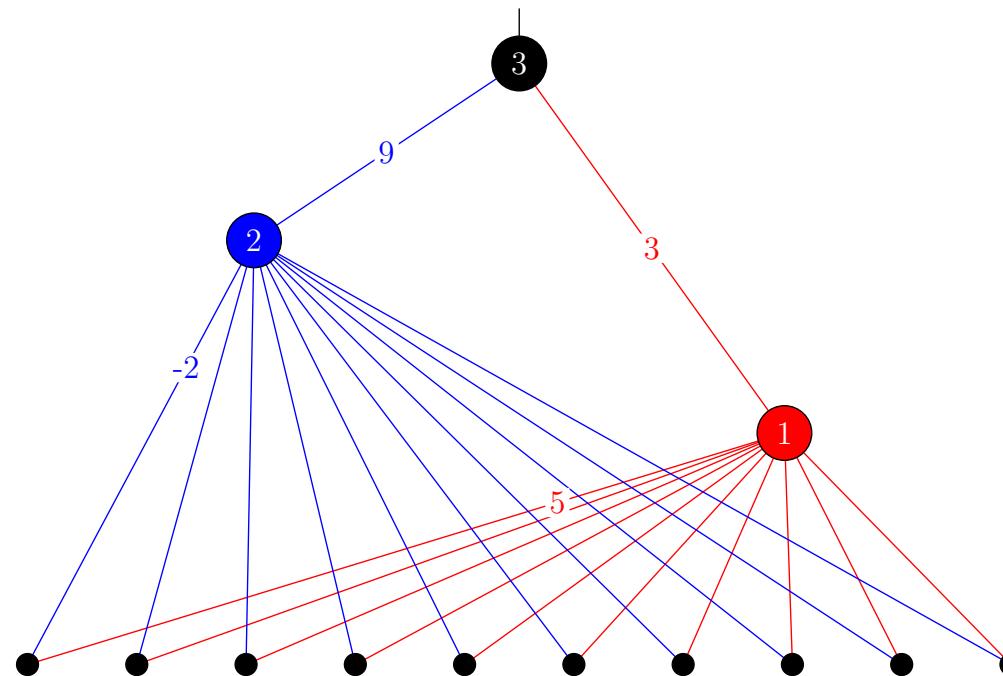
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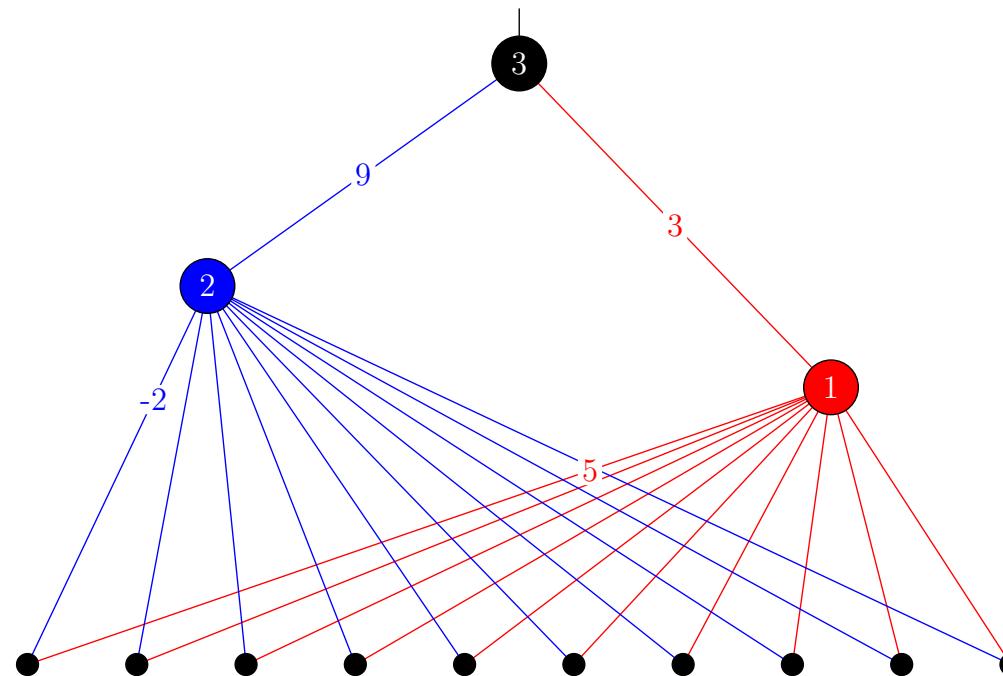
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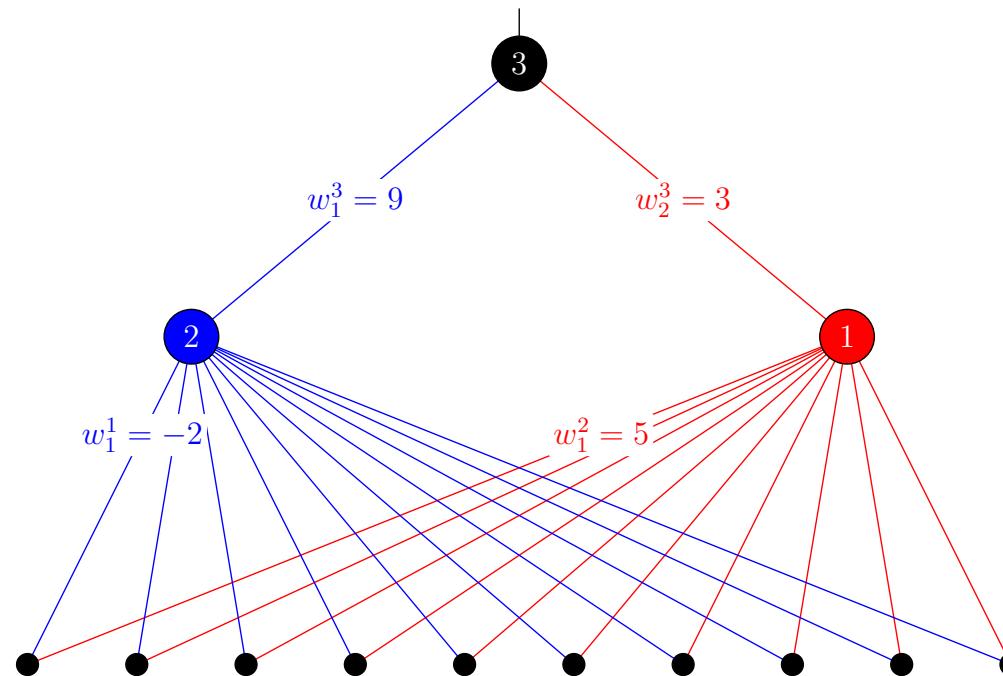
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# More Symmetries

- With  $n$  hidden nodes there are  $n!$  symmetries
- Often if I multiply all the input and output weights to a node by  $-1$  the network will be the same
- There are also continuous symmetries. For linear networks with two layers performing a mapping  $\mathbf{W}_2\mathbf{W}_1$  then for any invertible matrix  $\mathbf{U}$  (where  $\mathbf{U}\mathbf{U}^{-1} = \mathbf{I}$ )

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so a network with weights  $\mathbf{W}'_2 = \mathbf{W}_2\mathbf{U}$  and  $\mathbf{W}'_1 = \mathbf{U}^{-1}\mathbf{W}_1$  will perform the same mapping

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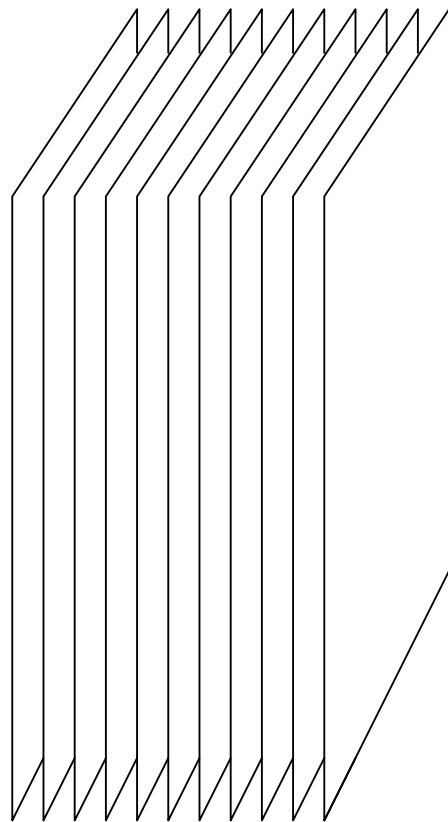
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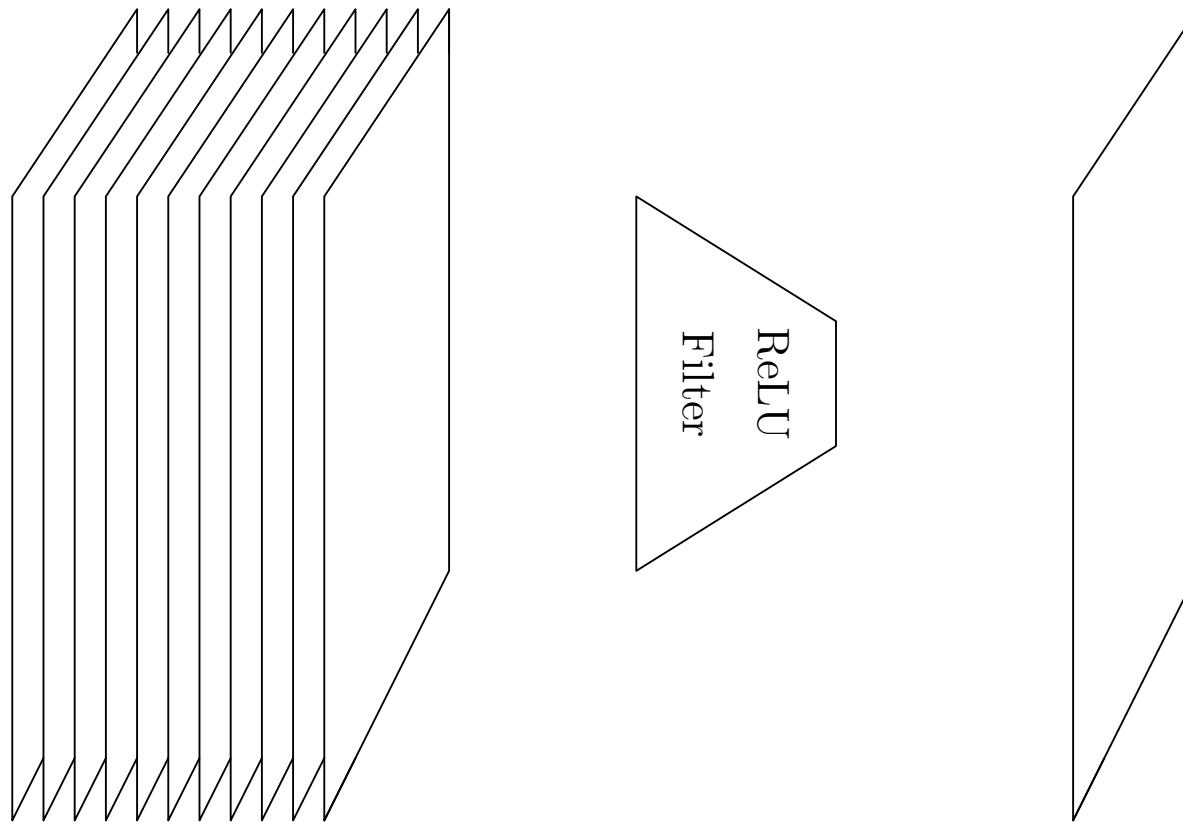
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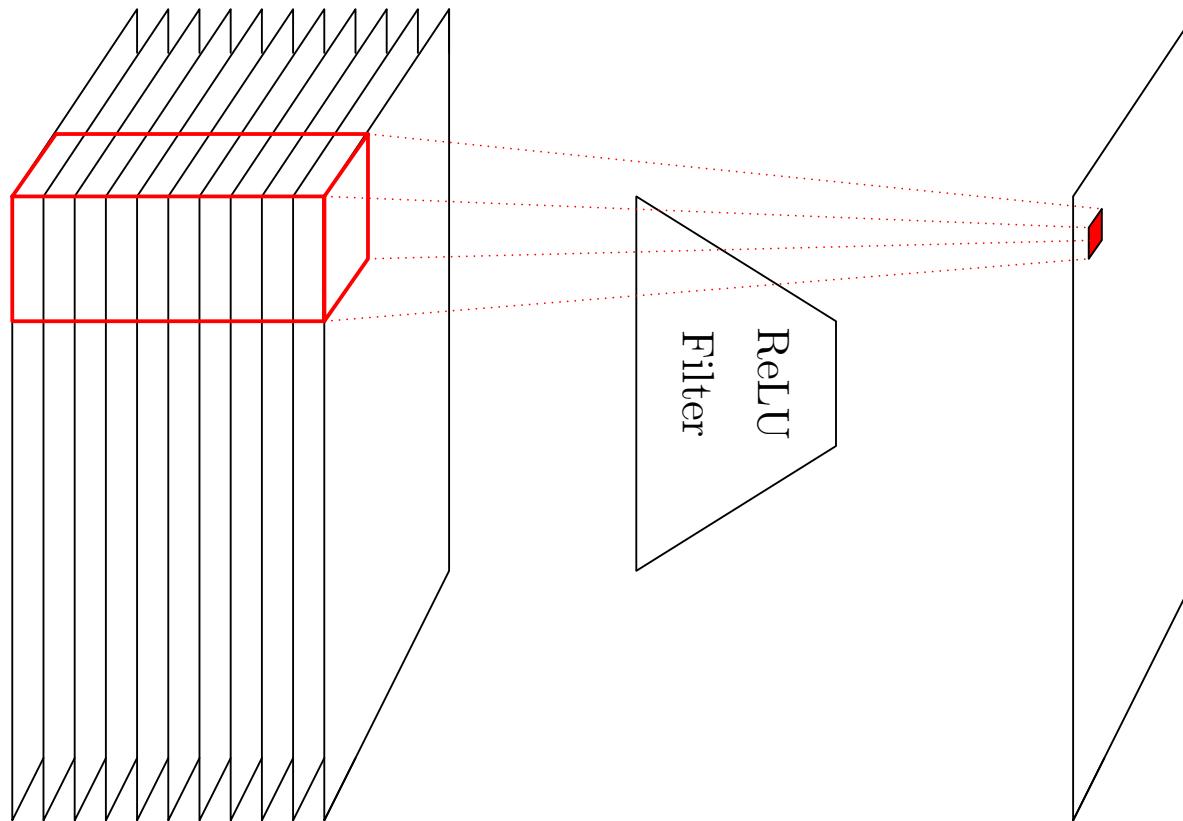
# Skip Connections



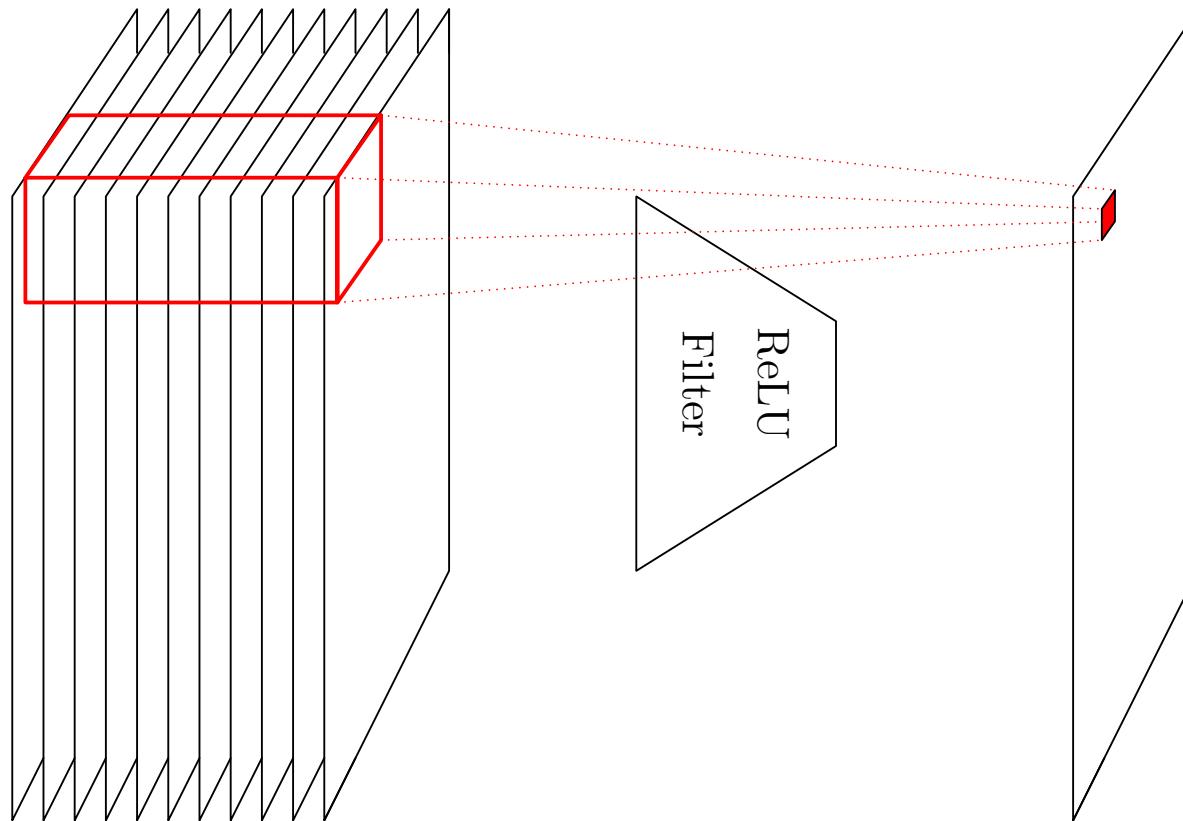
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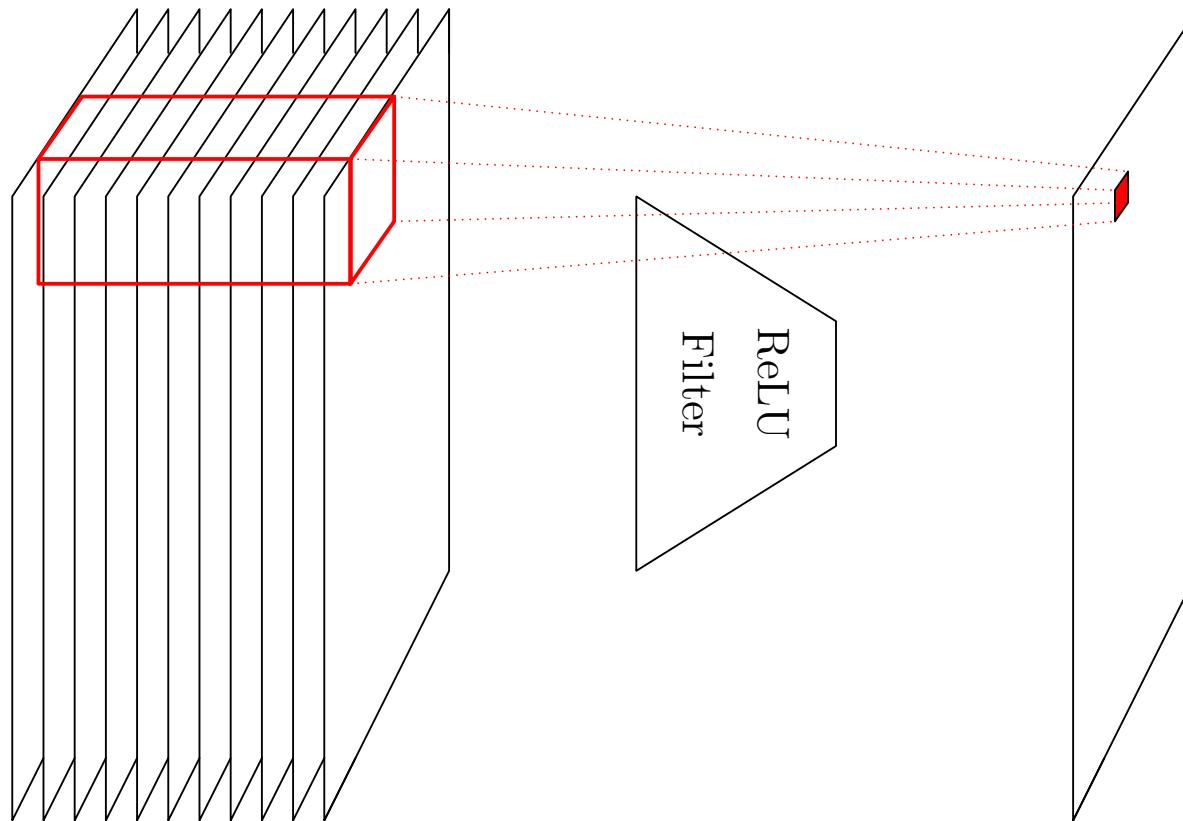
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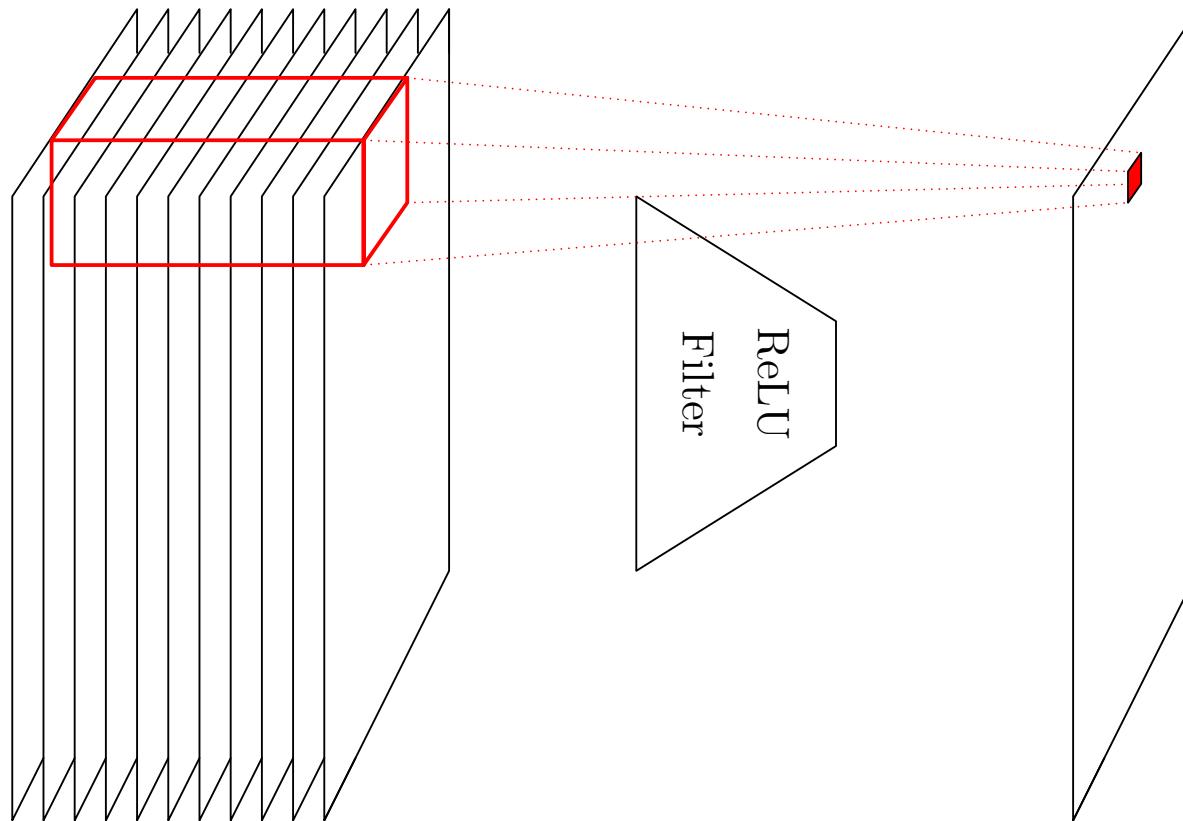
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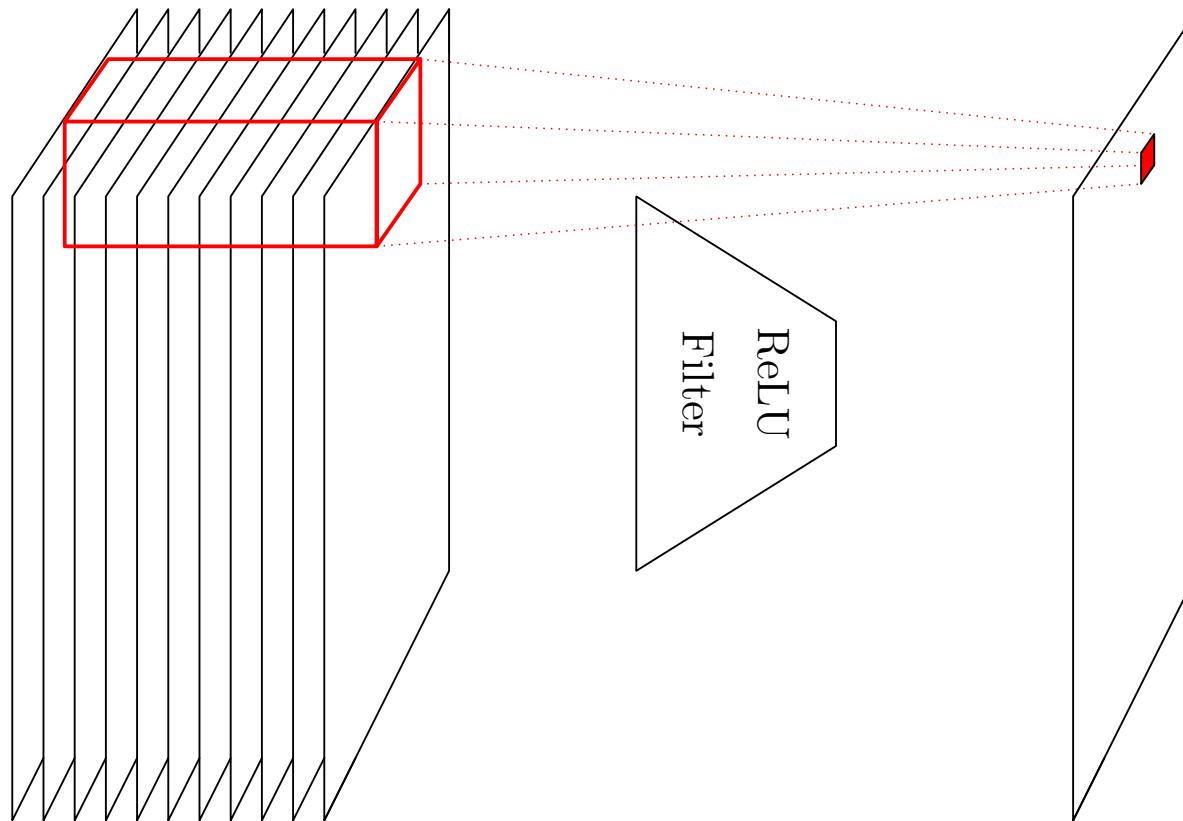
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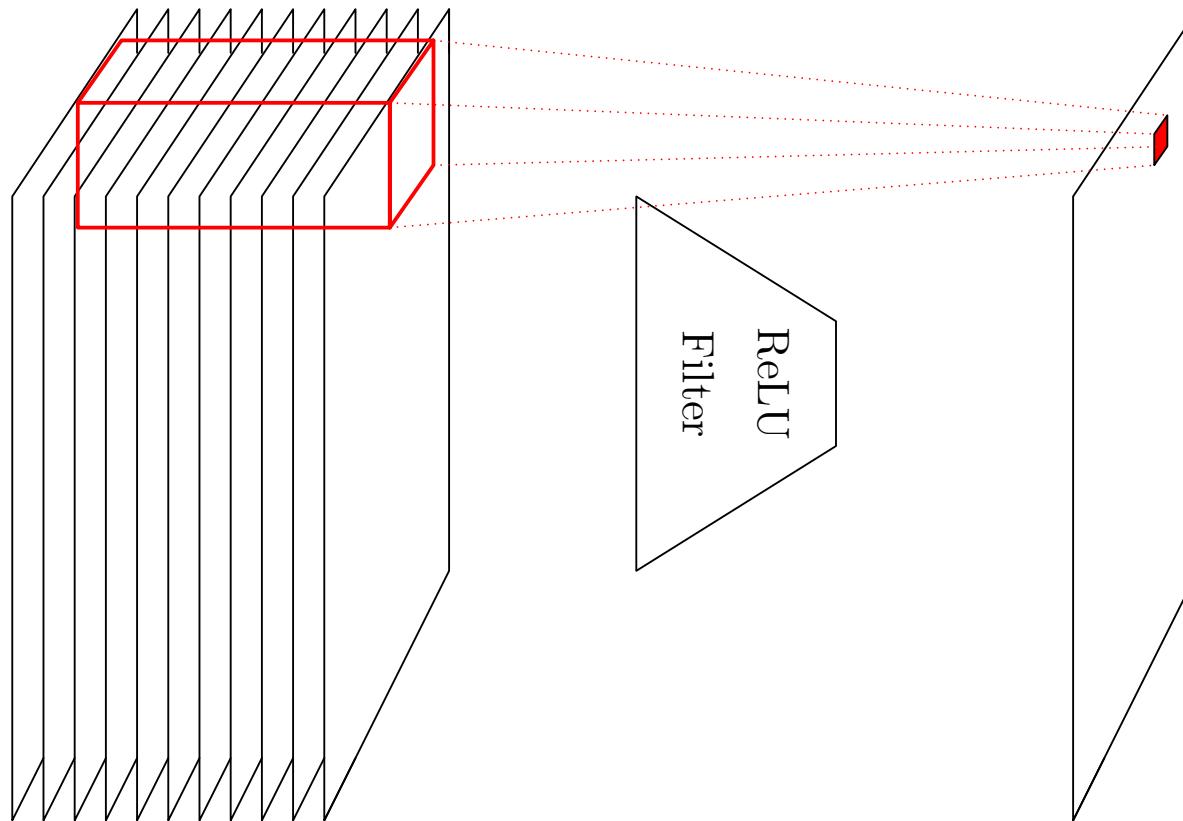
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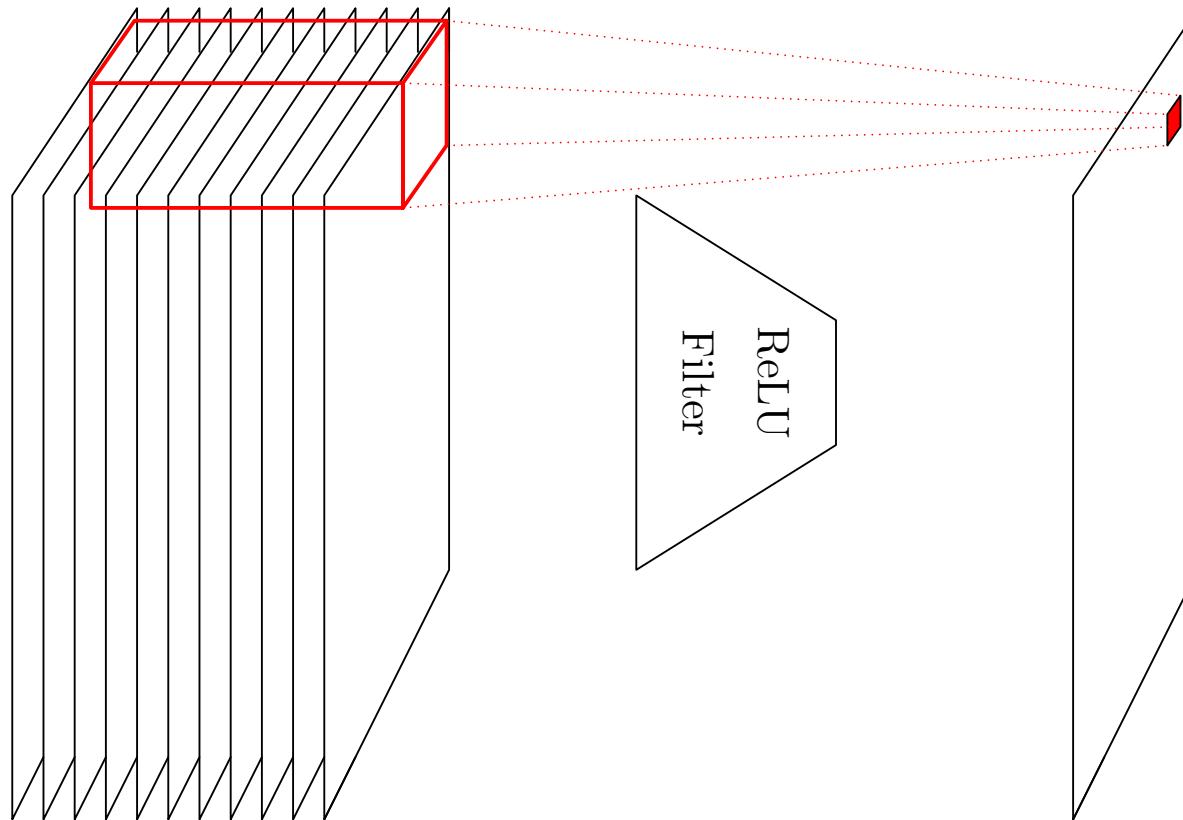
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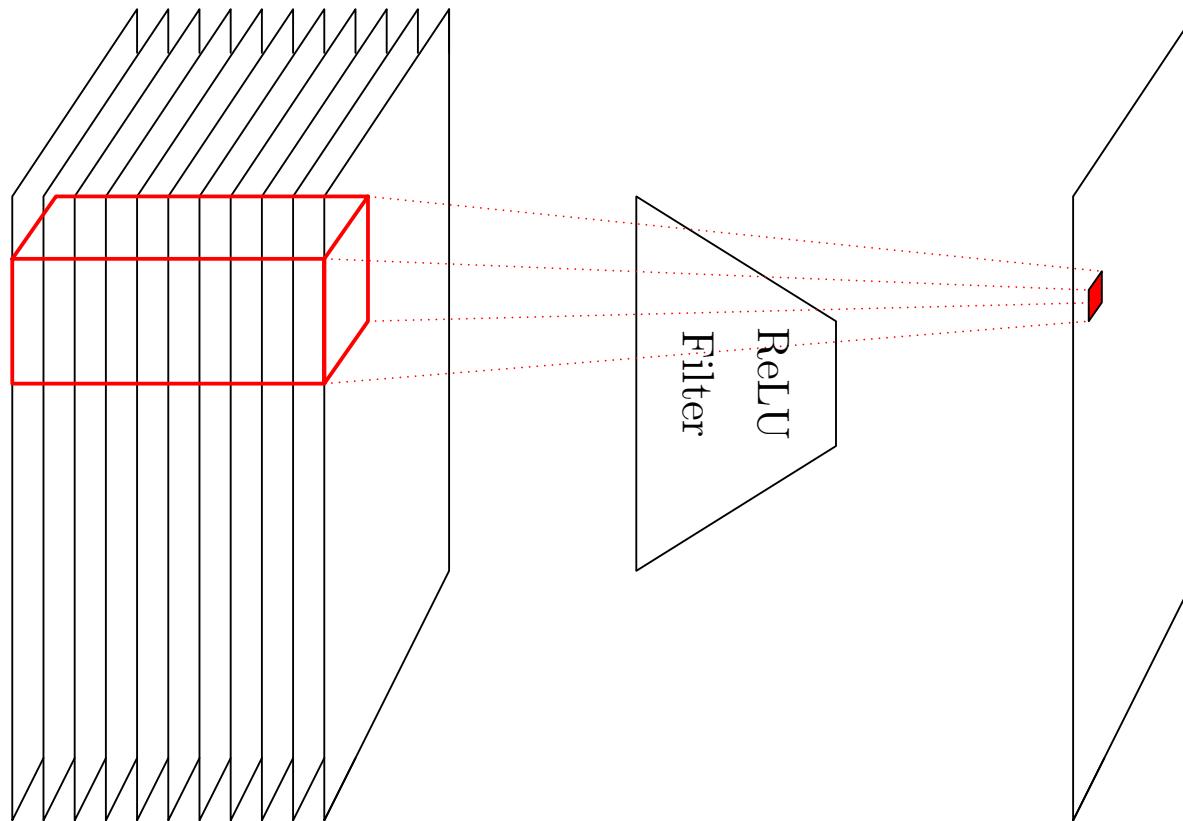
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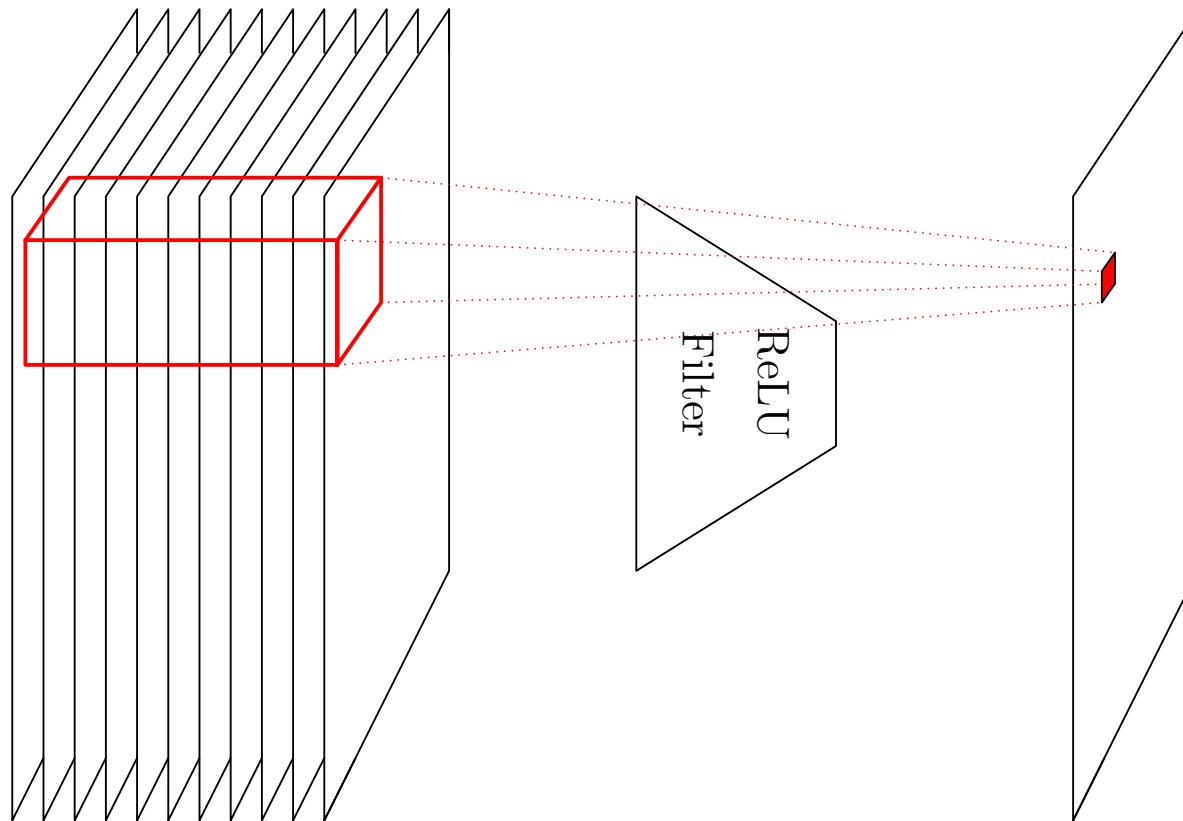
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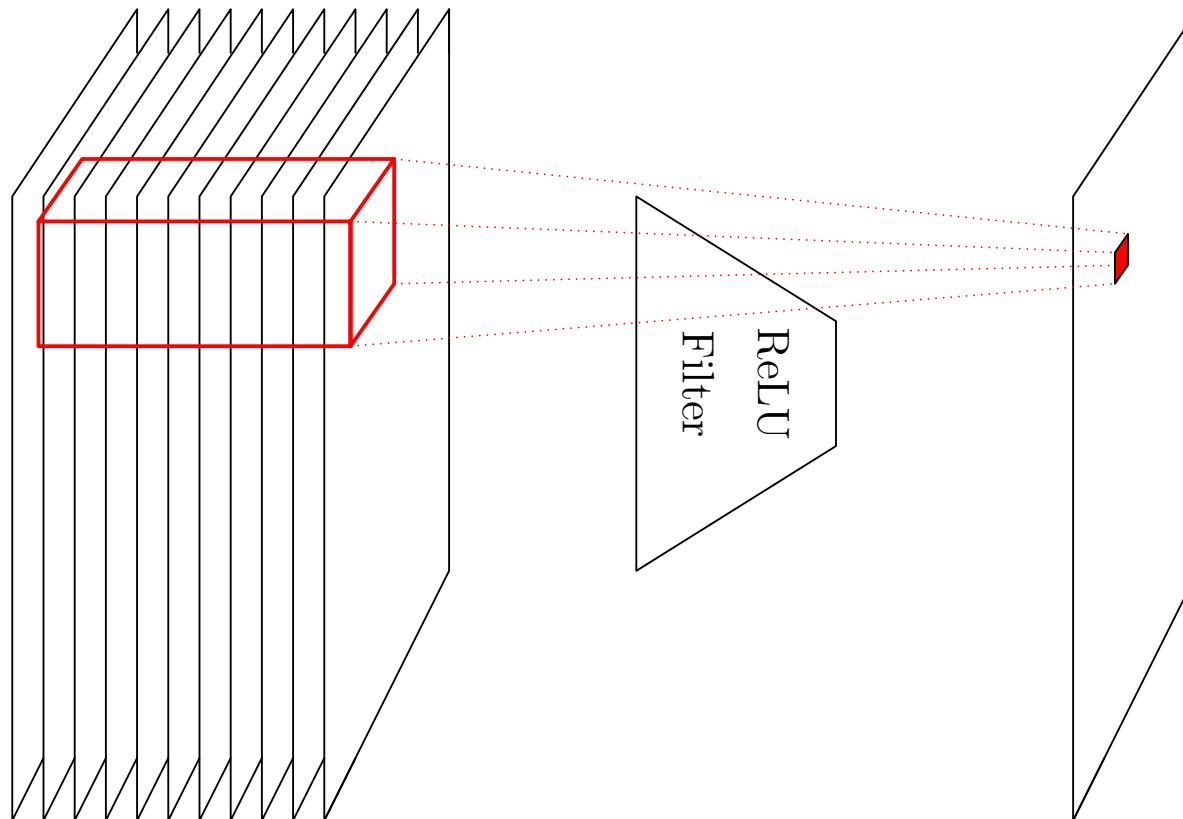
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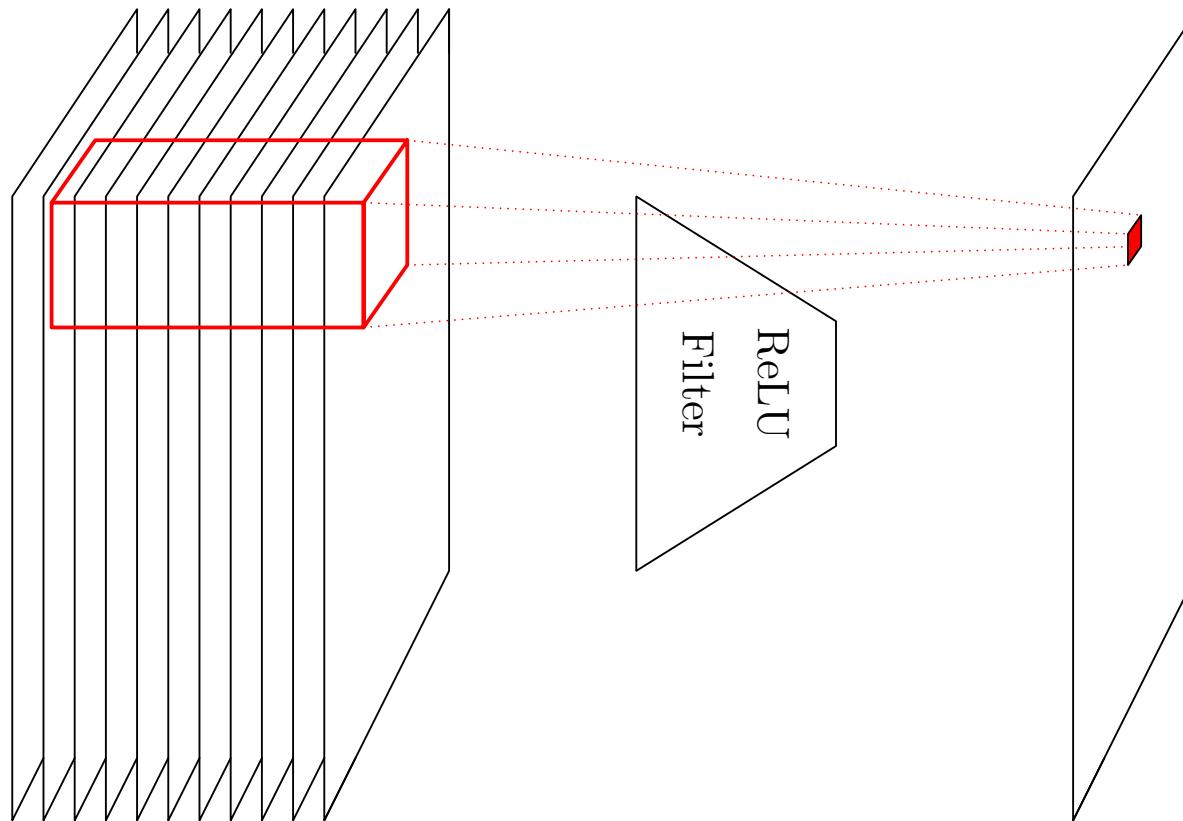
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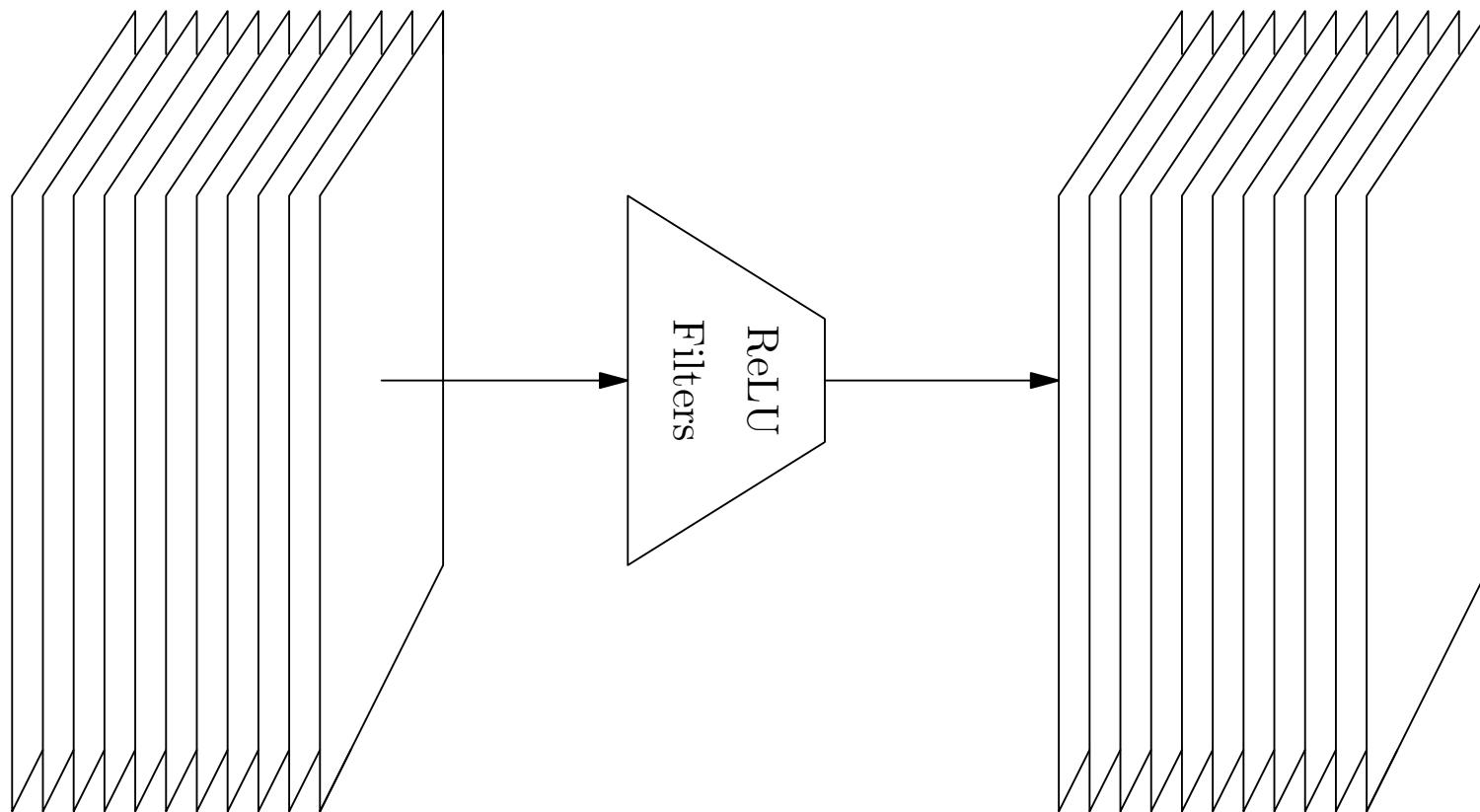
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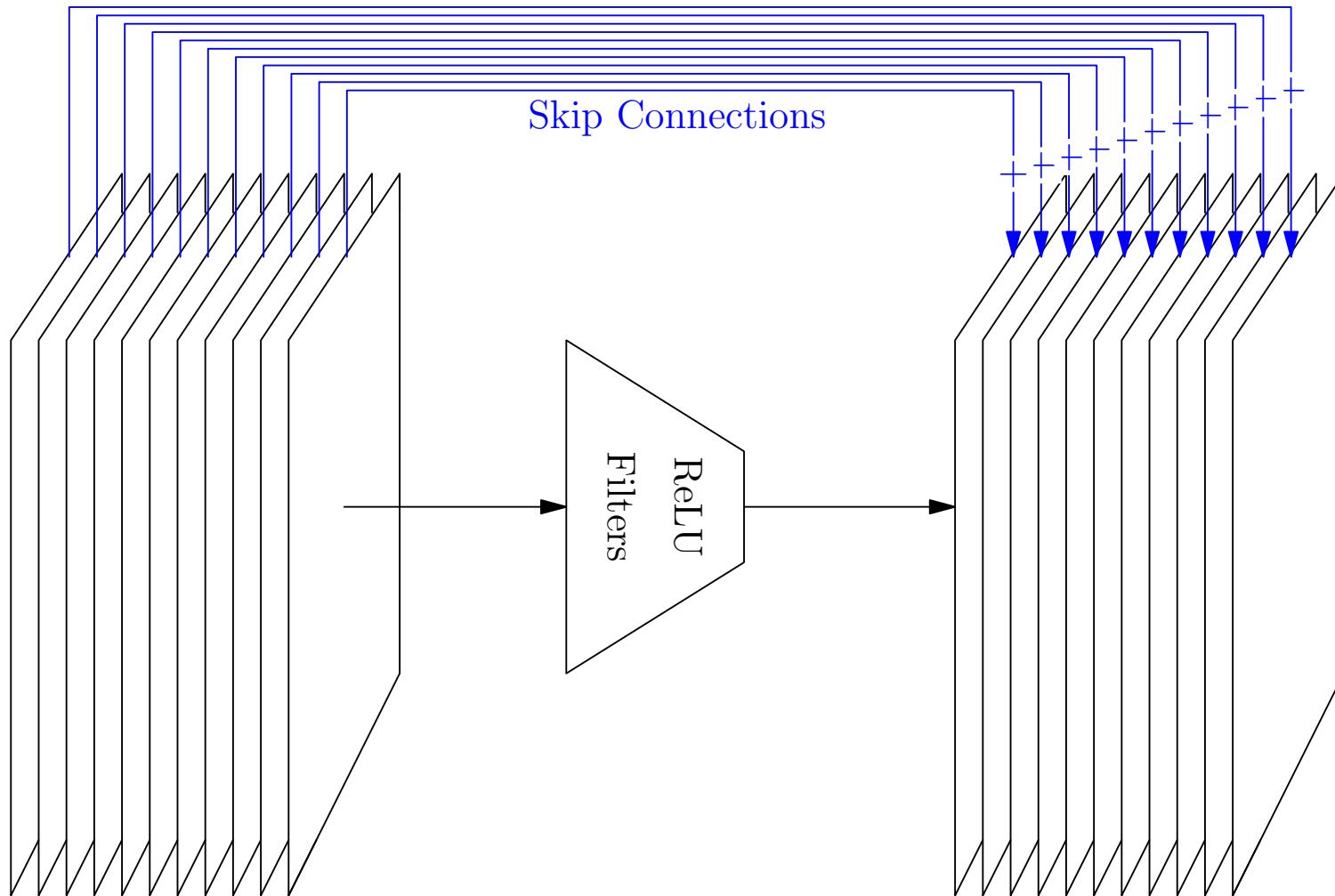
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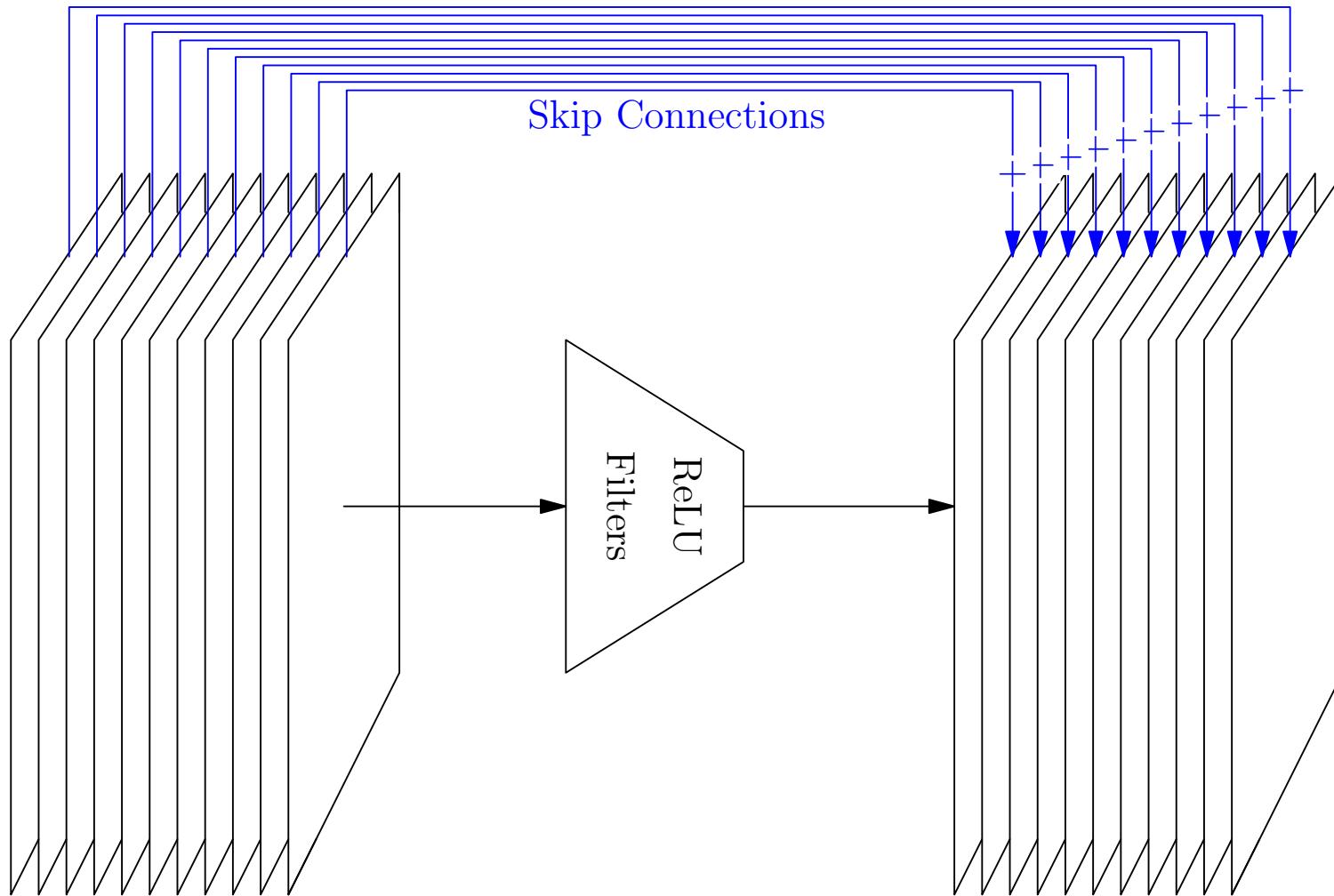
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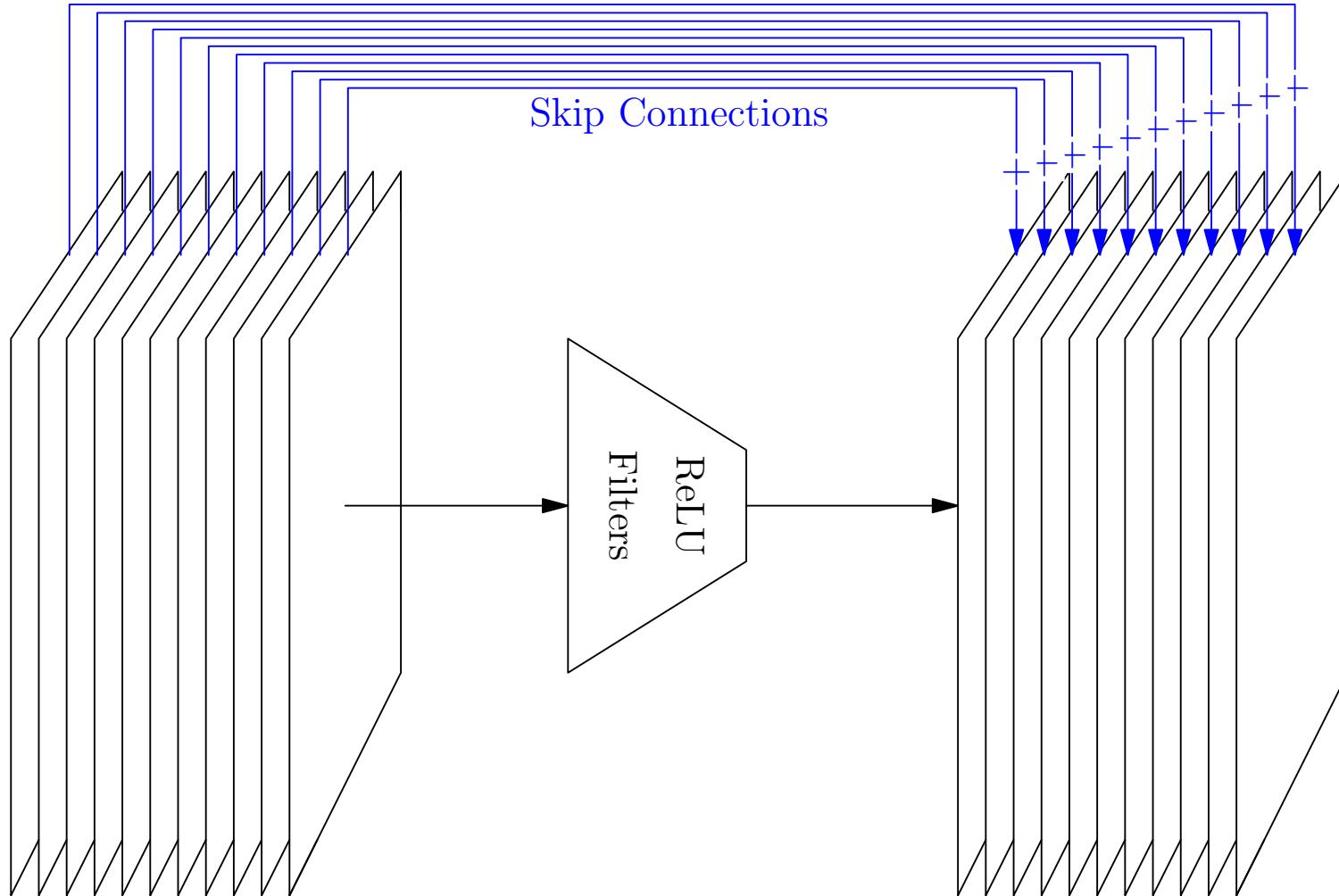


# Skip Connections



- Breaks permutation symmetry

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- Breaks permutation symmetry. Used in Resnets, transformer, etc.

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- The landscape potentially has a huge manifold with the same losses (neutral network)
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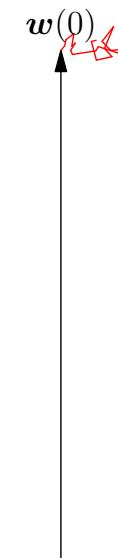
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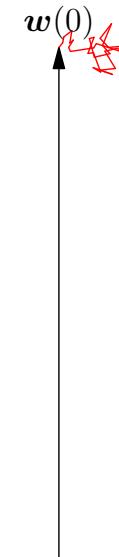
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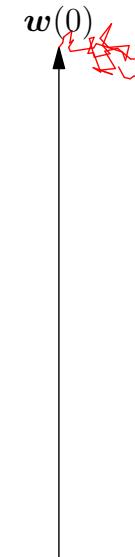
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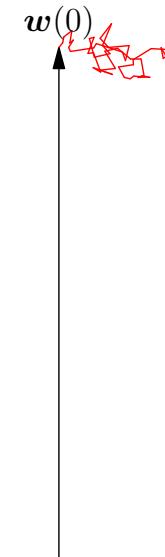
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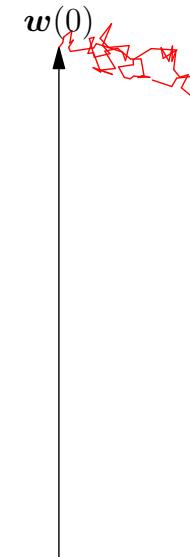
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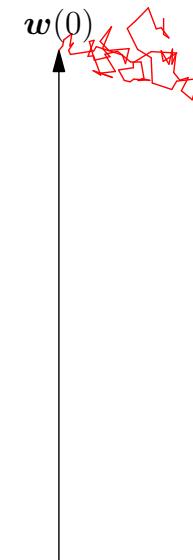
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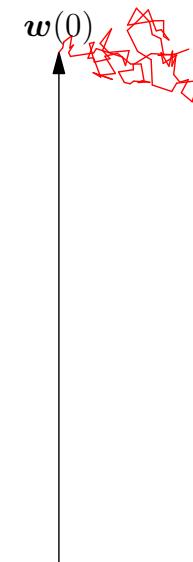
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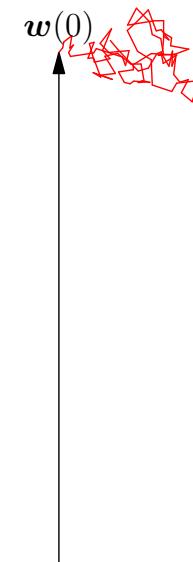
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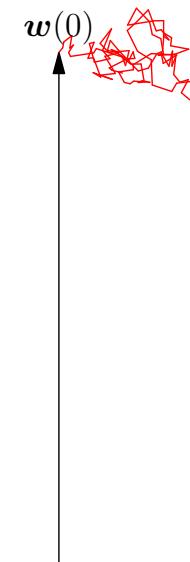
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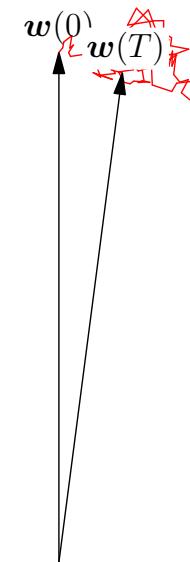
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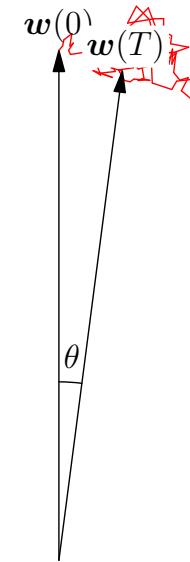
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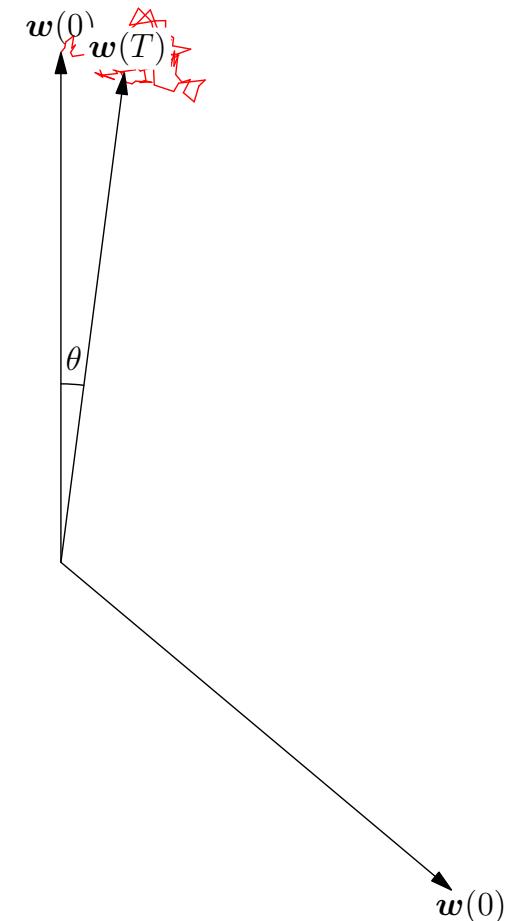
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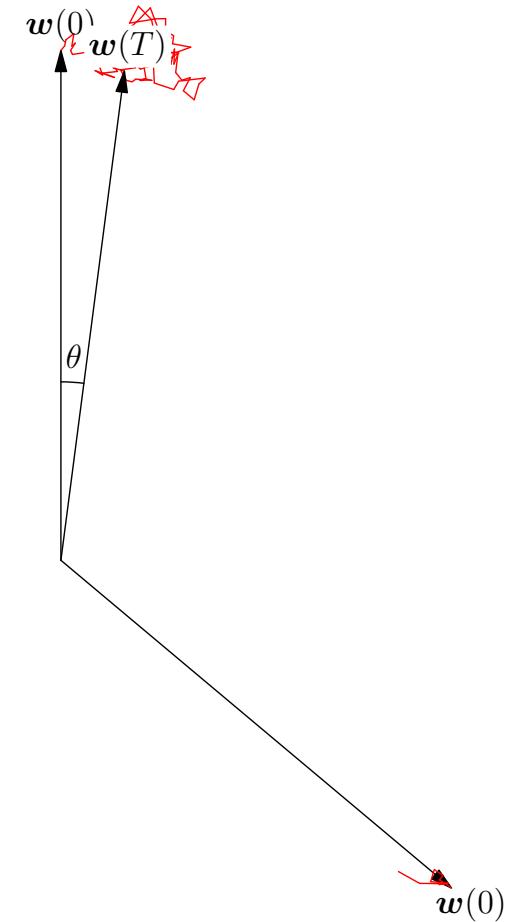
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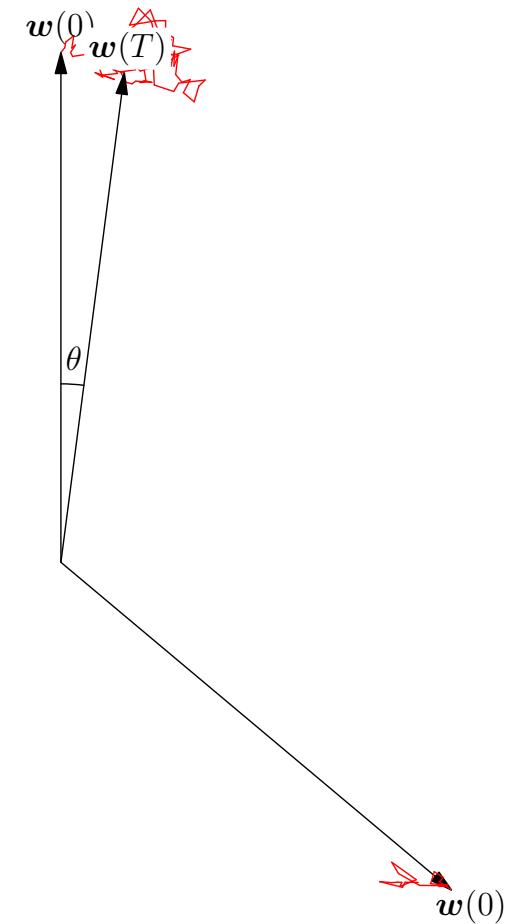
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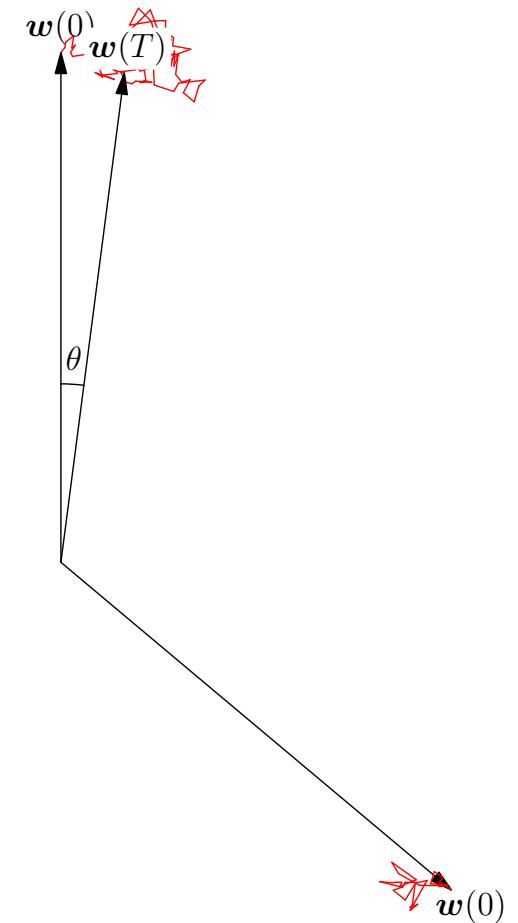
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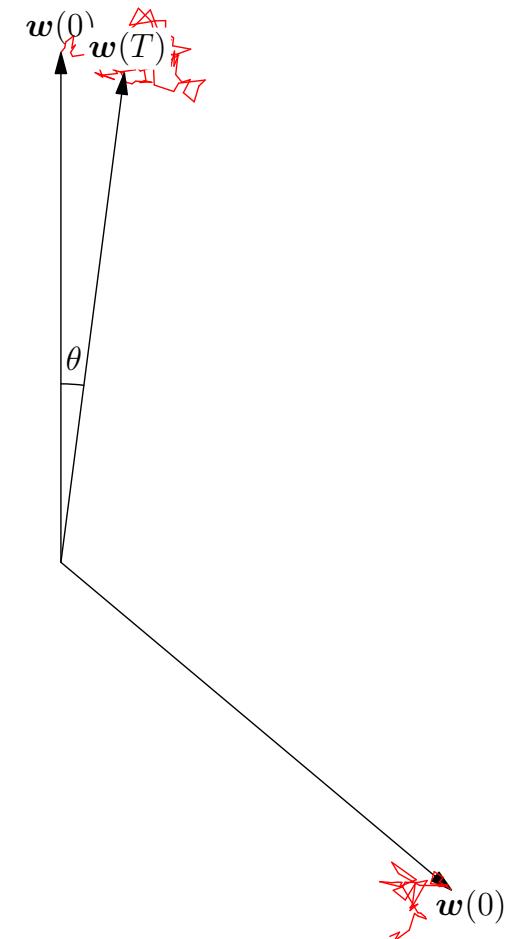
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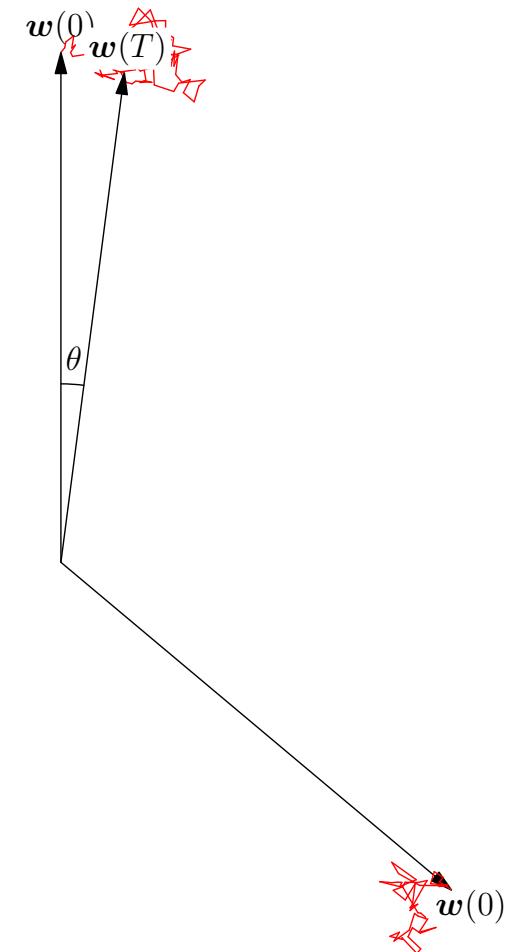
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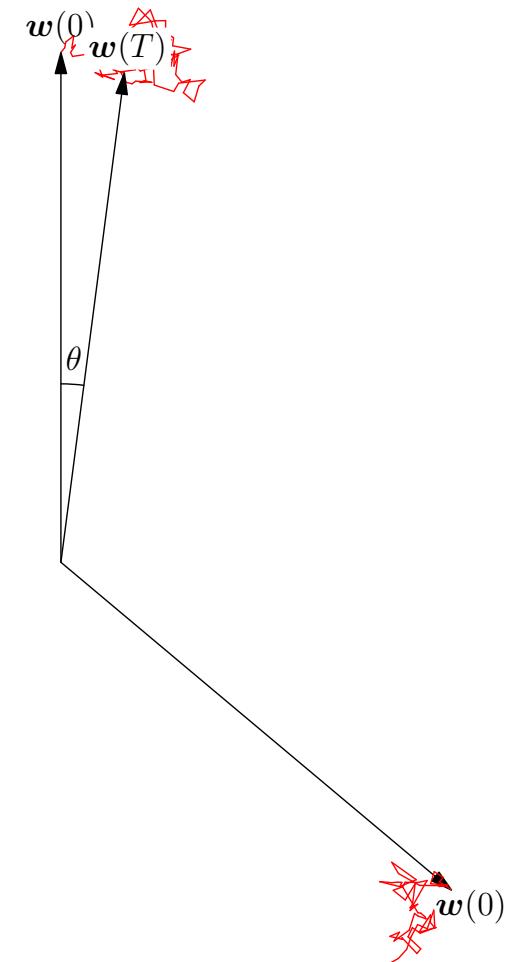
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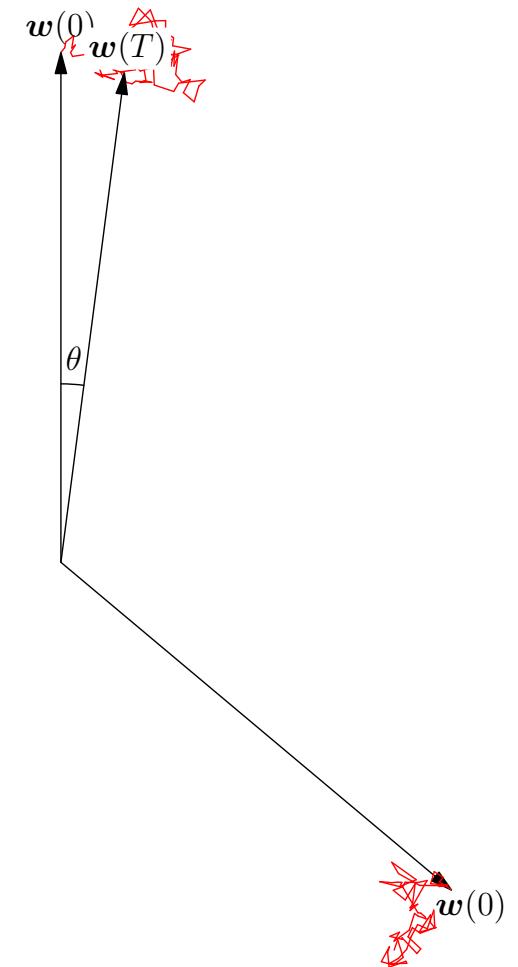
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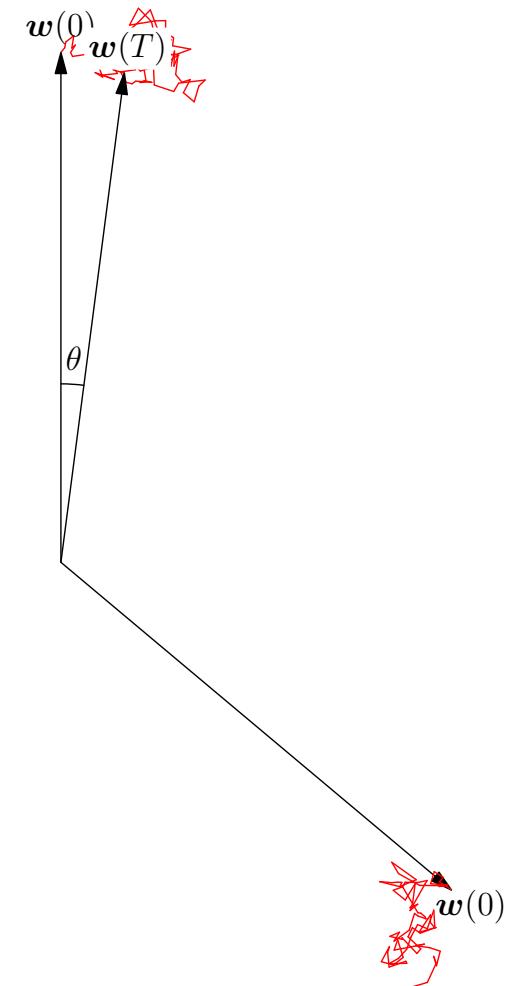
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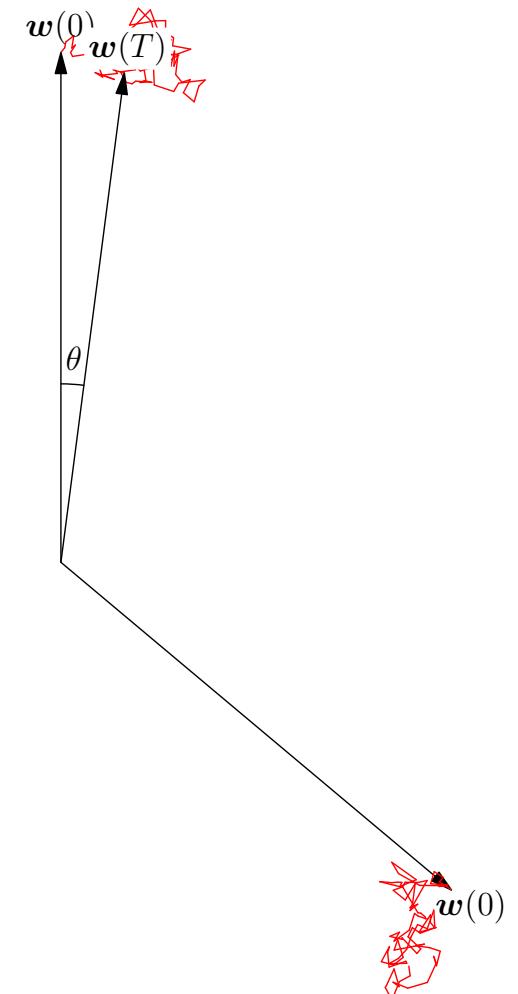
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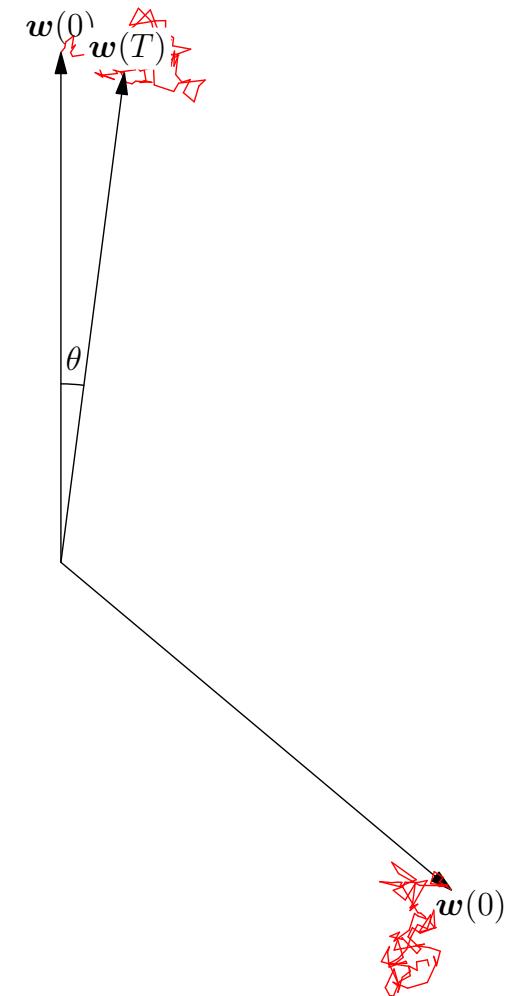
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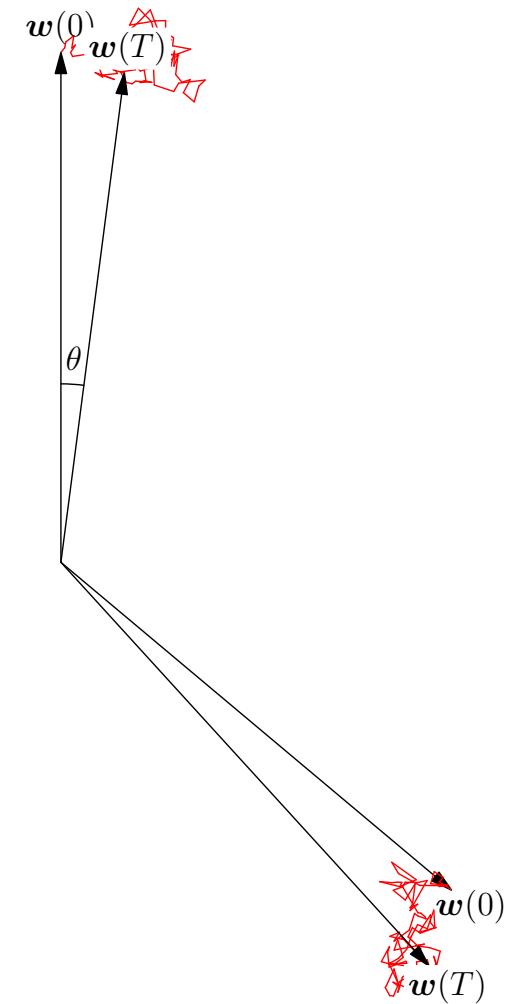
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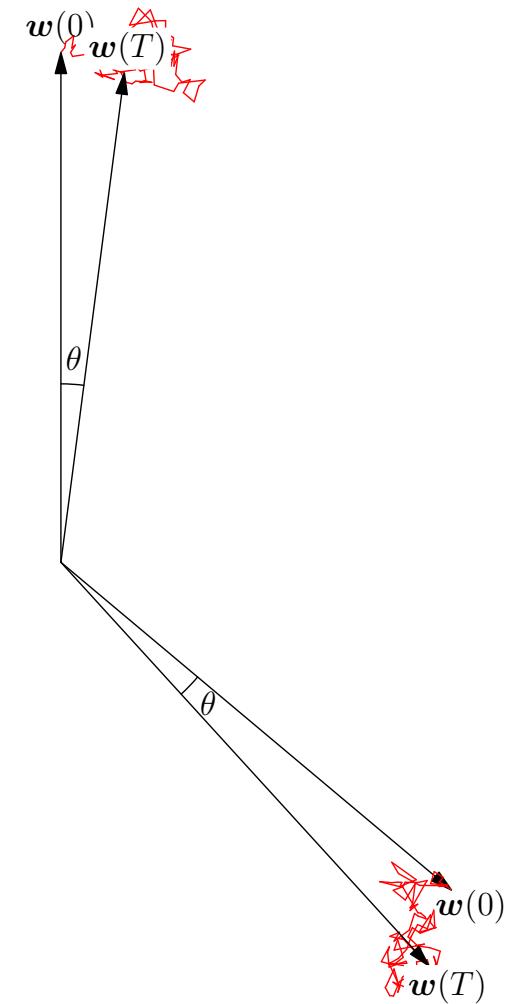
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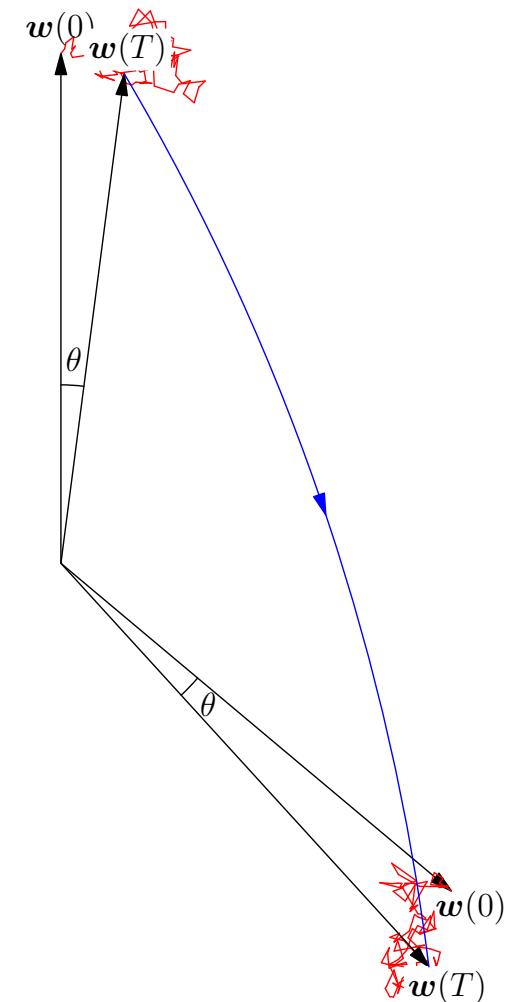
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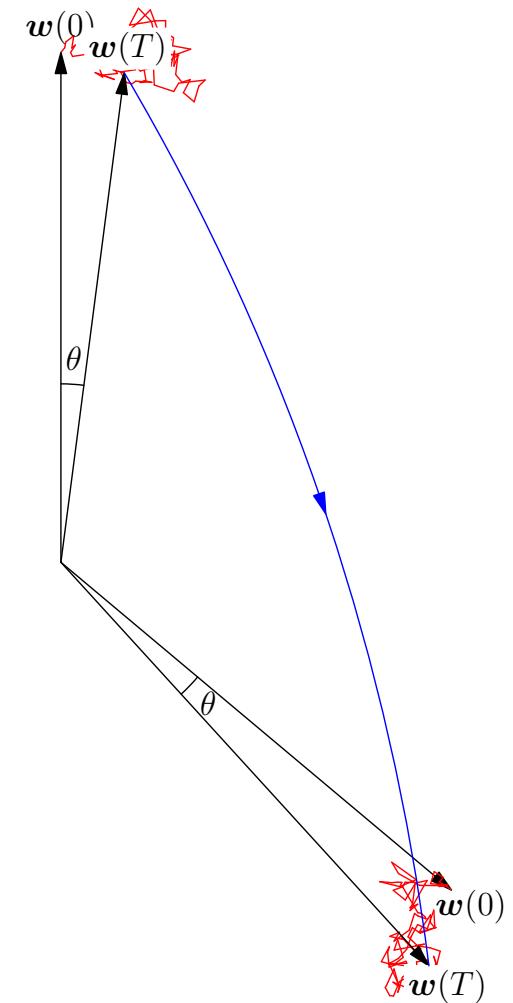
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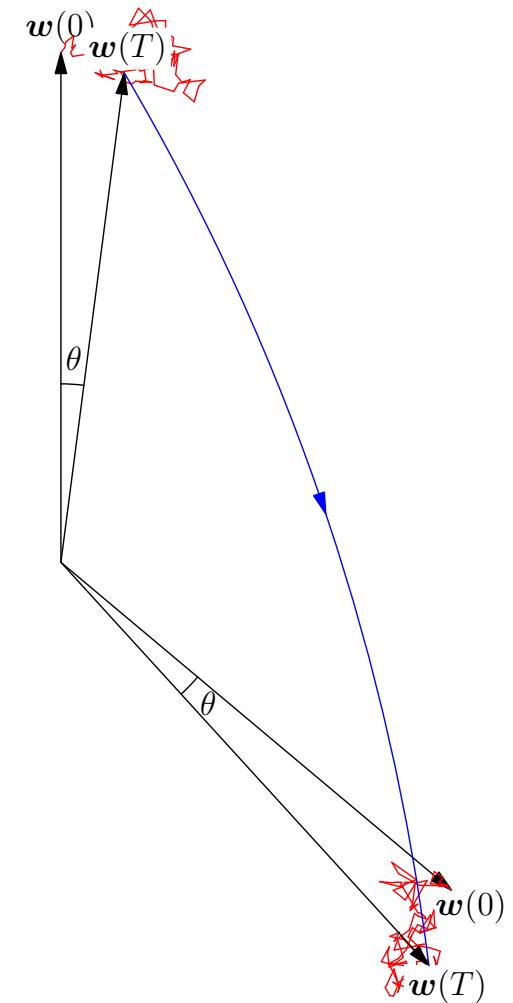
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