

Introduction to Deep Learning

Machine Learning

Linear Regression

$$\hat{y}_i = \sum_{j=1}^d x_{ij} \theta_j$$

d = input dimension

x = input data

θ = weights

Loss function:

$$J(\theta) = \frac{1}{n} \sum_{i=1}^n (\hat{y}_i - y_i)^2$$

in matrix notation:

$$J(\theta) = (\mathbf{X}\theta - \mathbf{y})^T (\mathbf{X}\theta - \mathbf{y})$$

differentiate:

$$\frac{\partial J(\theta)}{\partial \theta} = 2\mathbf{X}^T \mathbf{X} \theta - 2\mathbf{X}^T \mathbf{y} = 0$$

$$\theta = (\mathbf{X}^T \mathbf{X})^{-1} \mathbf{X}^T \mathbf{y}$$

Analytical solution for a convex problem.

Logistic Regression

$$\hat{\mathbf{y}} = p(\mathbf{y} = 1 | \mathbf{X}, \theta) = \prod_{i=1}^n p(y_i = 1 | \mathbf{x}_i, \theta)$$

where

$$\hat{y}_i = \sigma(\mathbf{x}_i \theta)$$

σ is the sigmoid/logistic function.

Loss function (binary cross entropy loss):

$$L(\hat{y}_i, y_i) = -[y_i \log \hat{y}_i + (1 - y_i) \log(1 - \hat{y}_i)]$$

No analytical solution. Iterative method needed (gradient descent).

Loss Functions

Measure the goodness of the prediction.

Large loss indicates bad performance.

Choice of loss function depends on problem.

Regression Loss

L1 Loss:

$$L(y, \hat{y}; \theta) = \frac{1}{n} \sum_i^n ||y_i - \hat{y}_i||_1$$

MSE Loss:

$$L(y, \hat{y}; \theta) = \frac{1}{n} \sum_i^n ||y_i - \hat{y}_i||_2^2$$

where

L1 norm (Manhattan distance):

$$||x||_1 = \sum |x_i|$$

- Promotes sparsity
- More robust to outliers

L2 norm (Euclidean distance):

$$||x||_2 = \sqrt{\sum x_i^2}$$

- Differentiable
- Penalizes large errors more heavily

Squared L2 norm:

$$||x||_2^2 = \sum x_i^2$$

- Differentiable

- Computationally efficient

Classification Loss

Binary Cross Entropy loss (binary classification):

$$L(y, \hat{y}; \theta) = -\frac{1}{n} \sum_i^n [y_i \log \hat{y}_i + (1 - y_i) \log(1 - \hat{y}_i)]$$

y is a probability output ($[0, 1]$) of the first class. Therefore, $1 - y$ is the probability of the second class. Works well with a sigmoid activation in the last layer.

Log penalizes bad predictions: $\log 0 = -\infty$, $\log 1 = 0$ (sort of inverts the prediction \hat{y}).

Encourages the model to make confident predictions close to 0 or 1.

Cross Entropy loss (multi-class classification):

$$L(y, \hat{y}; \theta) = - \sum_{i=1}^n \sum_{k=1}^k (y_{ik} \cdot \log \hat{y}_{ik})$$

The second sum is a generalization of the binary cross entropy case for multiple classes.

Backpropagation

Backpropagation aims to minimize the loss function by adjusting network weights and biases. The level of adjustment is determined by the gradients of the loss function with respect to those parameters.

Neural network is a chain of functions: linear transformations and activation functions. During backpropagation, the gradients of each linear transformation are calculated using the chain rule, starting from the derivative of the loss function and going backwards through the network.

Chain rule:

$$\frac{\partial y}{\partial x} = \frac{\partial y}{\partial u} \frac{\partial u}{\partial x}$$

or

$$h'(x) = f'(g(x))g'(x)$$

Calculate the gradients of the last layer:

$$\frac{\partial L}{\partial w_{ij}} = \frac{\partial L}{\partial \hat{y}_i} \cdot \frac{\partial \hat{y}_i}{\partial z_i} \cdot \frac{\partial z_i}{\partial w_{ij}}$$

where z are the outputs of the layer before the activation function.

For any weight update in the hidden layers, sum all gradients of all neurons that are influenced by that weight.

Useful Derivatives

ReLU:

$$\frac{\partial ReLU}{\partial x} = \text{if } x < 0 \text{ then } 0; \text{ if } x > 0 \text{ then } 1$$

Sigmoid:

$$\frac{\partial \sigma}{\partial x} = \sigma(x)(1 - \sigma(x))$$

Gradient descent

Gradient update step of the weight in direction of negative gradient (for a single training sample):

$$\theta^{k+1} = \theta^k - \alpha \nabla_{\theta} L_i(\theta^k, x_i, y_i)$$

where α is the learning rate, typically very small.

Update step for n samples:

$$\theta^{k+1} = \theta^k - \alpha \nabla_{\theta} L(\theta^k, x_{\{1..n\}}, y_{\{1..n\}})$$

where the gradient is the average over the residuals:

$$\nabla_{\theta} L(\theta^k, x_{\{1..n\}}, y_{\{1..n\}}) = \frac{1}{n} \sum_{i=1}^n \nabla_{\theta} L_i(\theta^k, x_i, y_i)$$

Potentially, the learning rate α could be calculated using Line Search:

$$\arg \min_{\alpha} L(\theta^k - \alpha \nabla_{\theta} L_i)$$

But this is not practical since we would need to solve a huge system every time.

The number of samples n is a hyperparameter called batch size.

Smaller batch size:

- Greater variance in the gradients, which leads to noisy updates
- slower convergence
- Needs more updates, but theoretically lower computational cost

Larger batch size:

- less variance in the gradients
- faster convergence
- higher computational cost, but we can use GPUs to parallelize the update

In practice, we want to choose the biggest possible batch size that can be parallelized on our GPUs in one backward pass. Often values such as 32, 64 up to 1024 are used, for large models the batch size could millions of samples.

Problems of Stochastic Gradient Descent:

- Gradient is scaled equally across all dimensions, cannot independently scale directions
- Learning rate needs to be conservative (small) to avoid divergence
- Small learning rate means slow convergence
- Finding the perfect learning rate is therefore difficult

Gradient Descent with Momentum

Instead of making many steps back and forth along the wrong dimensions, we would like to capture the momentum and move faster towards the optimum.

We calculate a velocity vector v :

$$v^{k+1} = \beta \cdot v^k - \alpha \cdot \nabla_{\theta} L(\theta^k)$$

which we use to update the weights:

$$\theta^{k+1} = \theta^k + v^{k+1}$$

Essentially, we add an exponentially-weighted average of the gradient. The hyperparameter β is usually set to 0.9.

Gradient descent with momentum can potentially overcome local minima due to the momentum factor, which allows it to escape "small bumps".

Nesterov Momentum

A kind of look-ahead momentum.

First make a big jump in the direction of the previously accumulated gradient:

$$\tilde{\theta}^{k+1} = \theta^k + \beta \cdot v^k$$

Then measure the gradient where you end up with the updated weights and make a correction:

$$v^{k+1} = \beta \cdot v^k - \alpha \cdot \nabla_{\theta} L(\tilde{\theta}^{k+1})$$

$$\theta^{k+1} = \theta^k + v^{k+1}$$

Regularization

Prevent overfitting with regularization.

Add regularization to the loss:

$$L'(y, \hat{y}; \theta) = L(y, \hat{y}; \theta) + \lambda R(\theta)$$

L2 Regularization:

$$R(\theta) = \sum_{i=1}^n \theta_i^2$$

- Is lower for smaller, distributed values.
- Enforces that weights have similar values.
- Model will take all information into account to make decisions.

L1 Regularization:

$$R(\theta) = \sum_{i=1}^n |\theta_i|$$

- Is overall lower than L2 with some higher weight values.
- Enforces sparsity.
- Model will focus attention on a few key features.

Regularization coefficient λ sets the level of regularization (higher λ means more regularization).

General effect of regularization: Lower validation error, but increased training error.