

# Deep Generative Modeling with Variational Auto-Encoders

Jakub M. Tomczak

What is **intelligence?**

What is **intelligence?**

...

# INFORMATION, INTELLIGENCE AND ARTIFICIAL INTELLIGENCE

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What is **artificial intelligence**?

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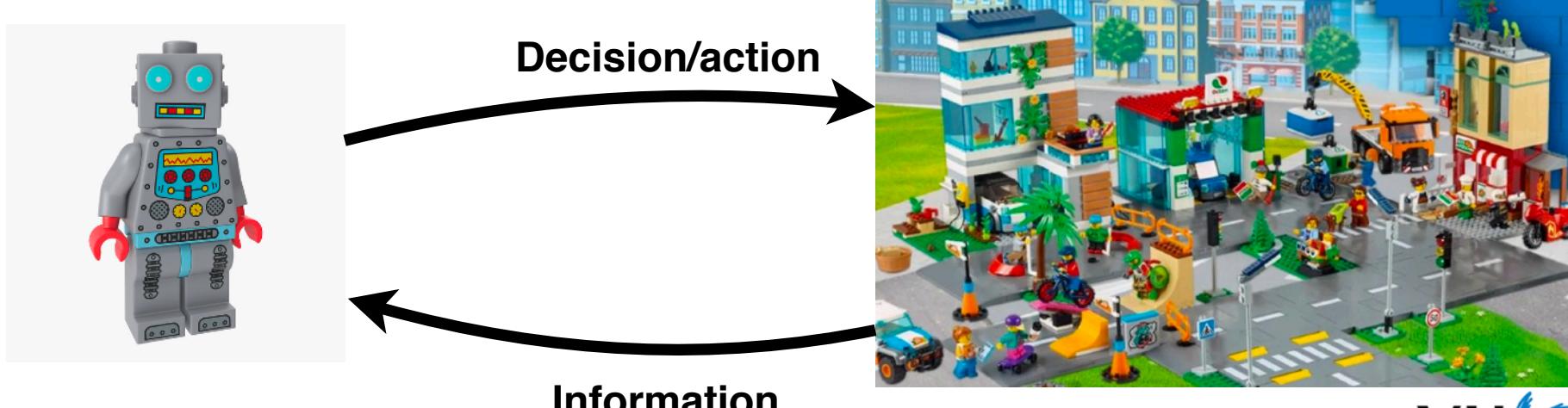


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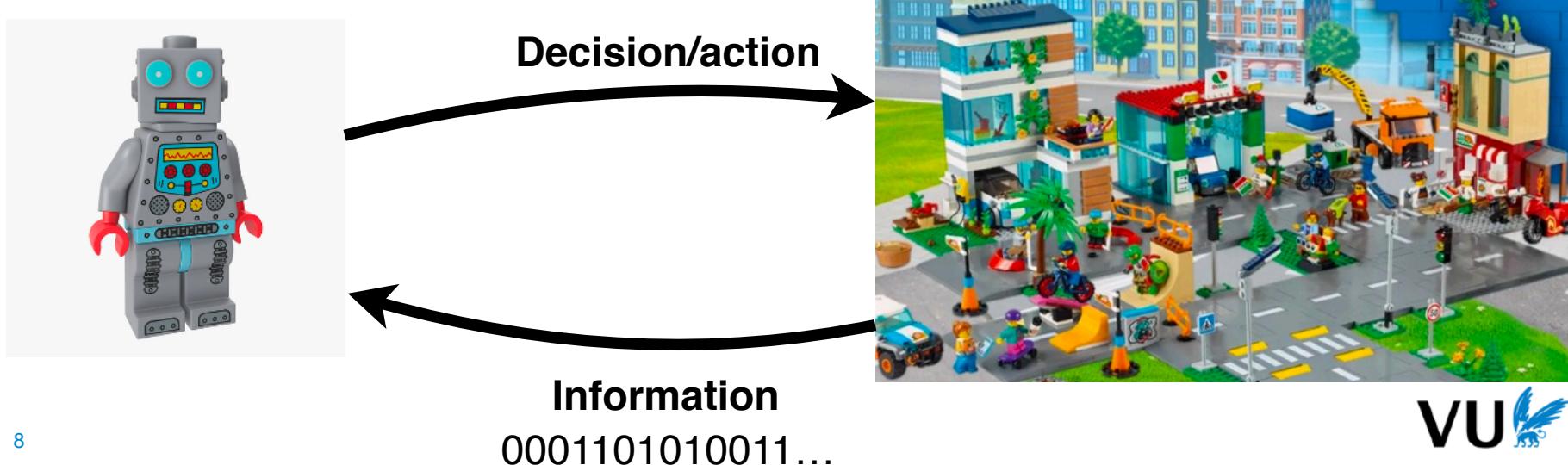


# INFORMATION, INTELLIGENCE AND ARTIFICIAL INTELLIGENCE

What is **intelligence**?

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What is **artificial intelligence**?



## What is **artificial intelligence**?

- **Information** processing
- **Information** storing
- **Information** transmission



## What is **artificial intelligence**?

- **Information** processing
- **Information** storing
- **Information** transmission
- **Decision** making



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- } Learning  
Knowledge representation  
Models...



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**The question is how to formalize the problem of AI?**

# INFORMATION, INTELLIGENCE AND ARTIFICIAL INTELLIGENCE

## Information (a quick recap)



Claude Shannon

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We have a random source of data  $x$ .



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We can quantify the **uncertainty** of this source by calculating **the entropy**:



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$$\mathbb{H}[x] = - \sum_x p(x) \log p(x)$$

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**Entropy is max if all  $x$ 's are equiprobable.**

**Entropy is min if the probability of one value is 1.**

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**Optimal message length  $\approx$  the entropy.**

# INFORMATION, INTELLIGENCE AND ARTIFICIAL INTELLIGENCE

## Information (a quick recap)

We have two random sources:  $x$  and  $y$ .

We can quantify the **uncertainty** of them by calculating  
**the joint entropy**:



Claude Shannon

$$\mathbb{H}[x, y] = - \sum_{x,y} p(x, y) \log p(x, y)$$

or **the conditional entropy**:

$$\mathbb{H}[y | x] = - \sum_{x,y} p(x, y) \log p(y | x)$$

## Mutual Information (a quick recap)

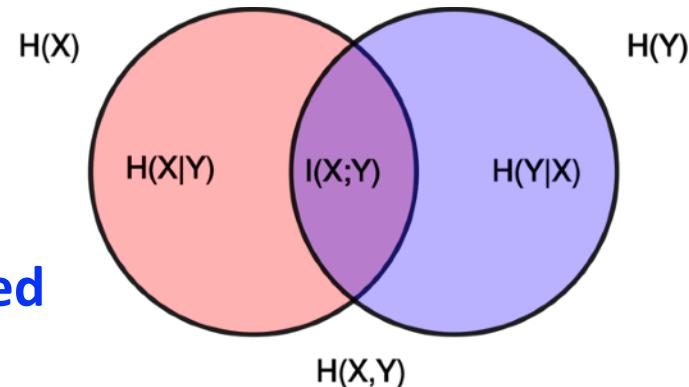
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$$I[x; y] = H[y] - H[y | x]$$

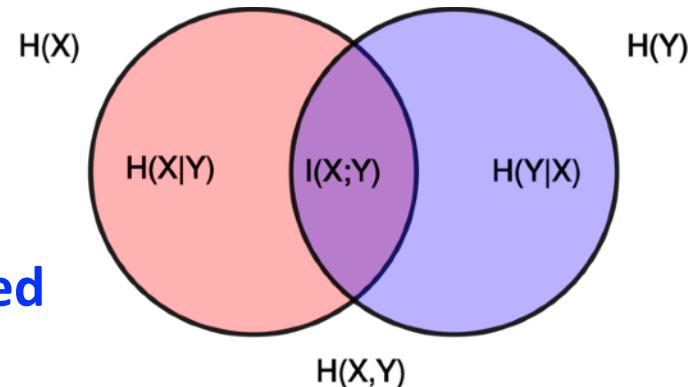


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## Mutual Information (a quick recap)

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We can quantify how much **information is shared by the two sources:**



$$I[x; y] = H[y] - H[y | x]$$

or **how much knowing one source reduces uncertainty about the other.**

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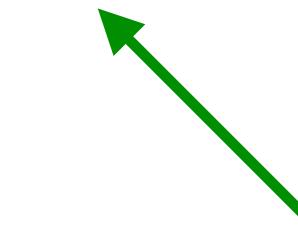
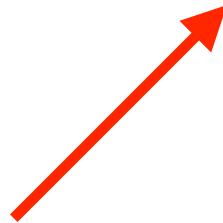
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$$\mathbb{I}[(x, y); m] = \mathbb{H}[x, y] - \mathbb{H}[x, y | m]$$

Entropy of the world  
(model has no influence on that)



That's the “real” goal!

The **goal** of AI is to **maximize** the **mutual information** between  $(x, y)$  and  $m$

(or minimize  $\mathbb{H}[x, y \mid m]$ , i.e., minimize uncertainty of the world):

$$\mathbb{H}[x, y \mid m] = \sum_{x,y,m} p(x, y, m) [\log p(y \mid x, m) + \log p(x \mid m)]$$

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A model for  
decision making



A model for  
understanding  
the world.

The **goal** of AI is to **maximize** the **mutual information** between  $(x, y)$  and  $m$  (or minimize  $\mathbb{H}[x, y \mid m]$ , i.e., minimize uncertainty of the world).

In order to achieve that, AI should focus on learning **two models**:

- **A model for decision making:**  $p(y \mid x, m)$
- **A model for understanding the world:**  $p(x \mid m)$

## WHAT HAPPENS IF WE LEARN ONLY DECISION MAKING

The bulk of AI is focused on the decision making part **only**!

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Example: Let's say we have a model that is well trained.



$$p(y = \text{cat}|\mathbf{x}) = 0.90$$

$$p(y = \text{dog}|\mathbf{x}) = 0.05$$

$$p(y = \text{horse}|\mathbf{x}) = 0.05$$

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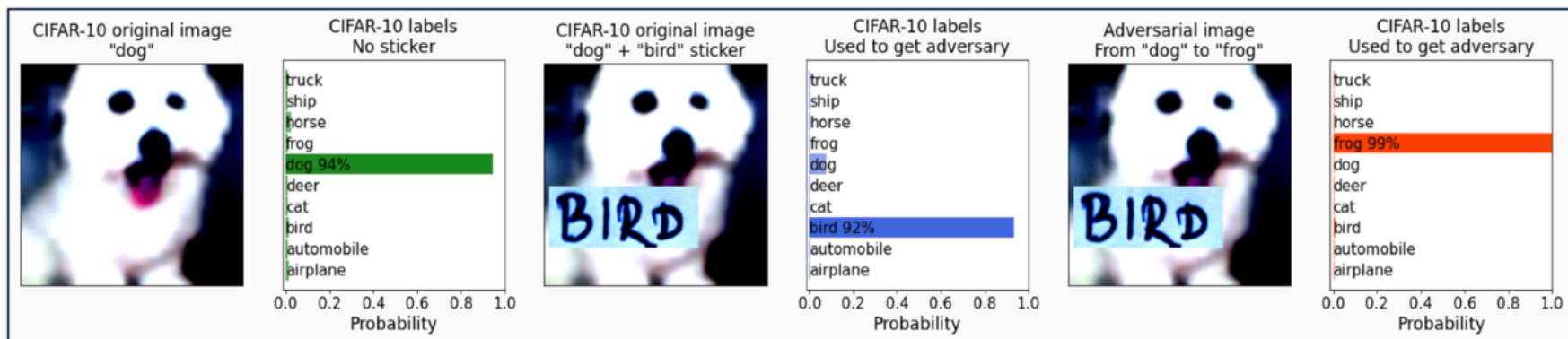
$$\begin{aligned} p(y = \text{cat}|\mathbf{x}) &= 0.05 \\ p(y = \text{dog}|\mathbf{x}) &= 0.05 \\ p(y = \text{horse}|\mathbf{x}) &= 0.90 \end{aligned}$$

But after adding a little noise it could fail completely...

# IS LEARNING CLASSIFIERS ENOUGH?

Let's assume we have a perfectly trained neural net.

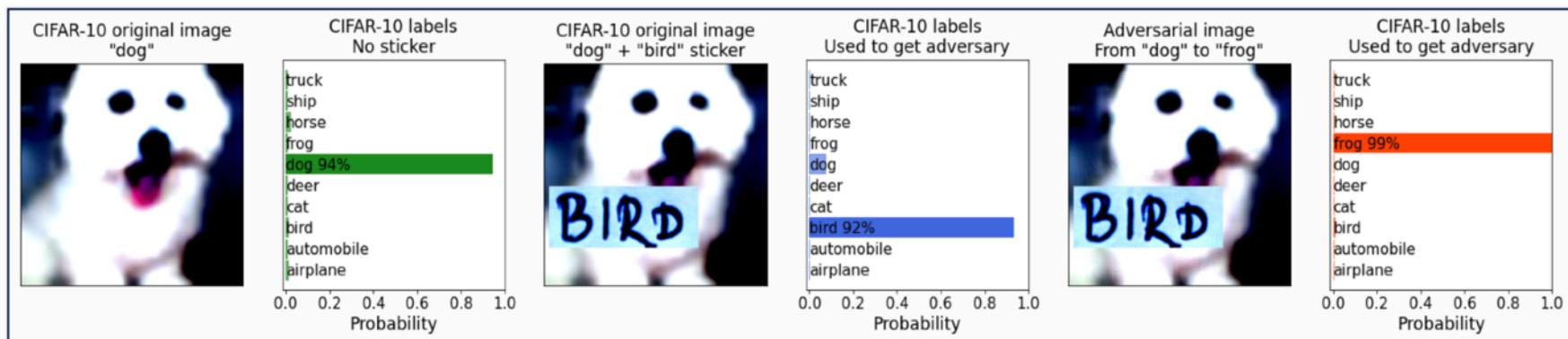
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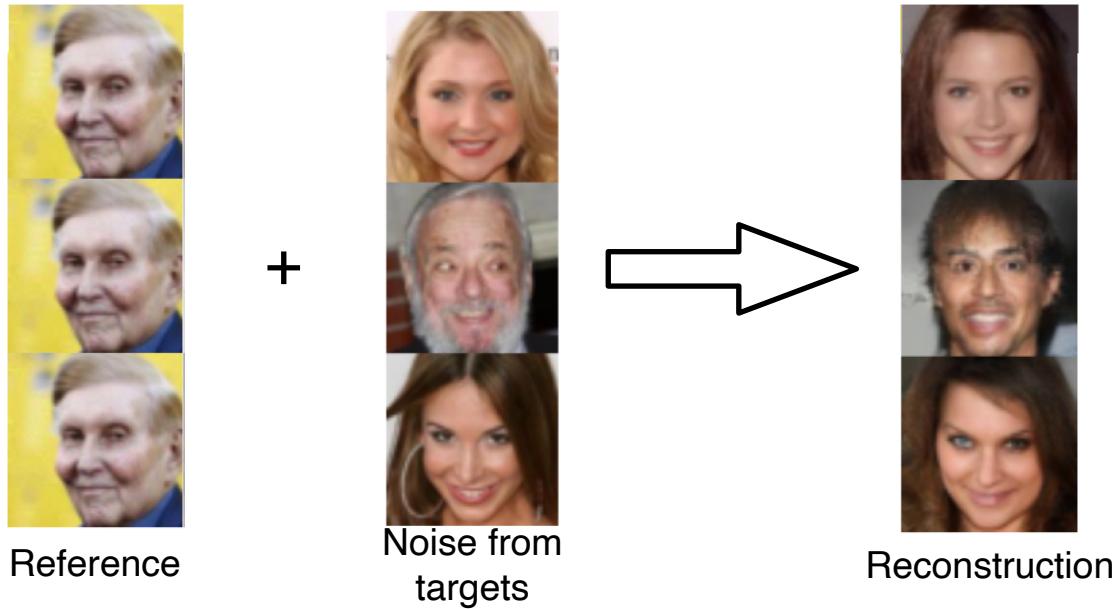
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<sup>33</sup>S. Fort, "Pixels still beat text: Attacking the OpenAI CLIP model with text patches and adversarial pixel perturbations", [\[Link\]](#)

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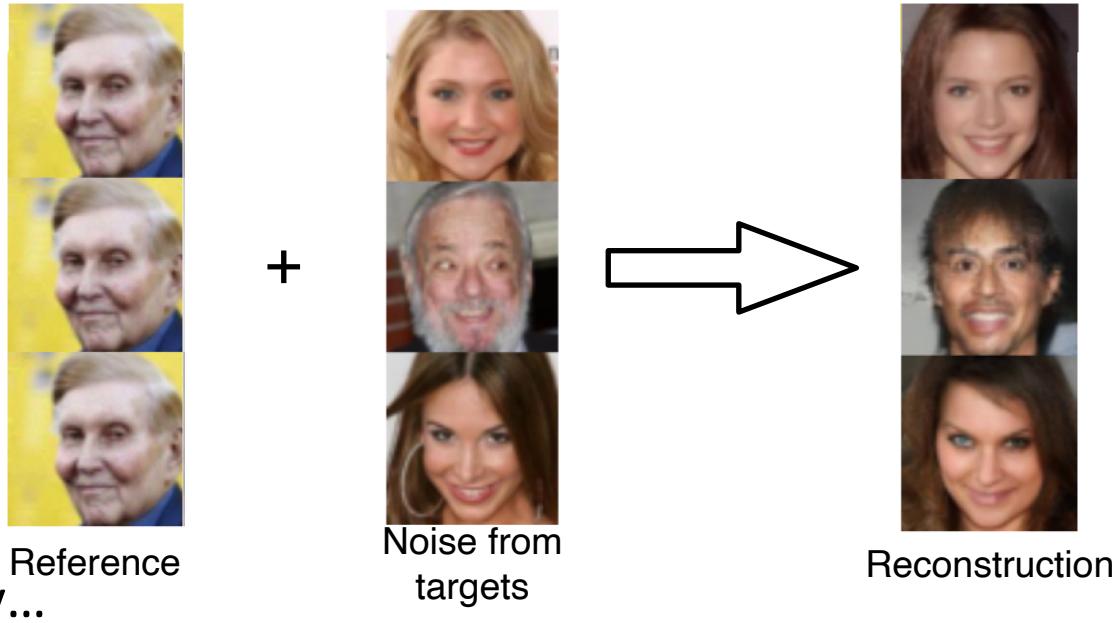


<sup>34</sup>A. Kuzina, M. Welling, J.M. Tomczak, “Diagnosing Vulnerability of Variational Auto-Encoders to Adversarial Attacks”, [\[Link\]](#)

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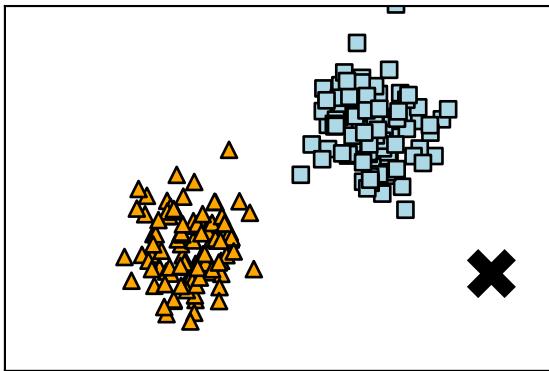
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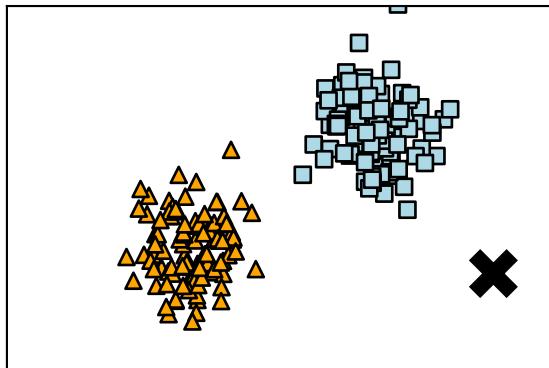
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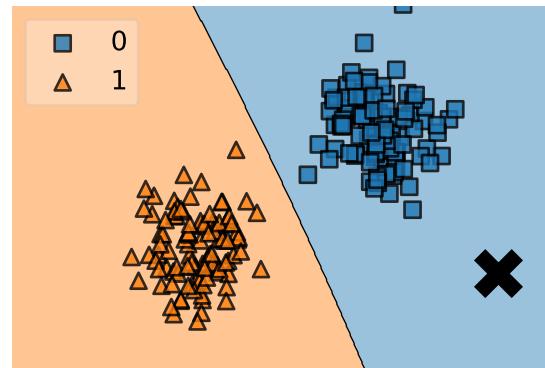
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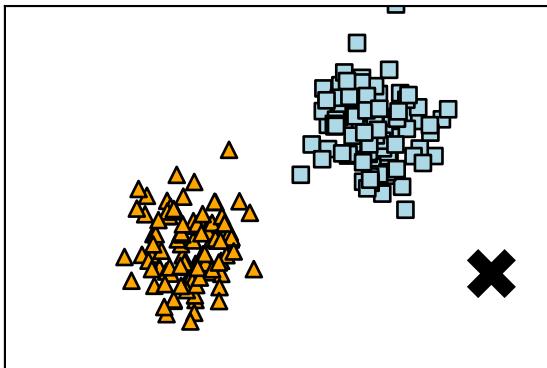
Data



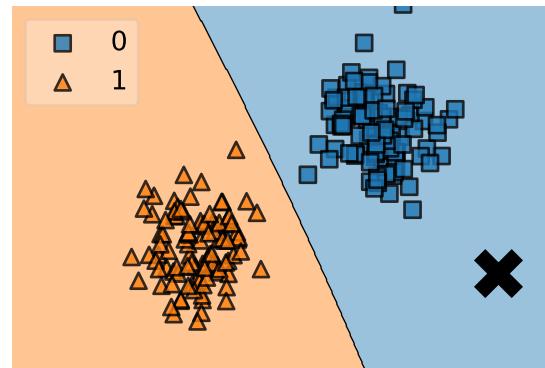
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$p(\text{blue}|\mathbf{x})$  is high  
= certain decision!

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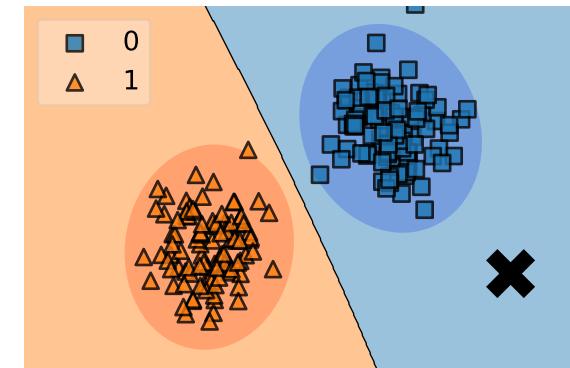


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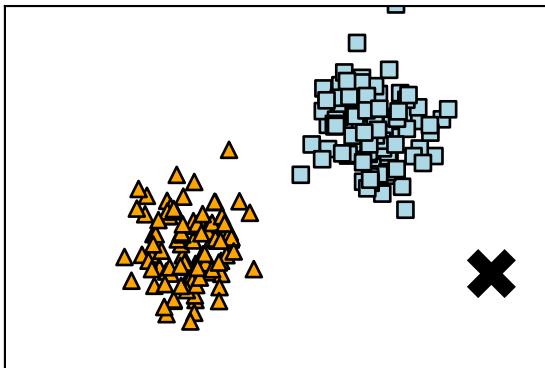
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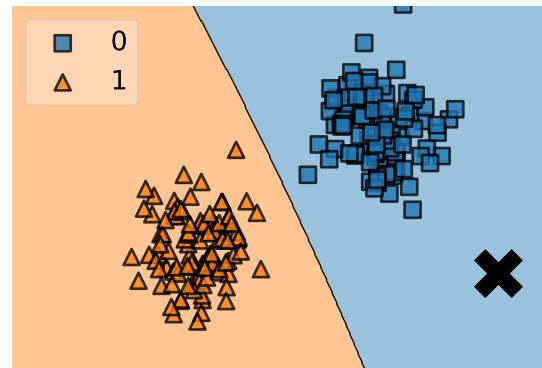
$p(\mathbf{x}, y) = p(y|\mathbf{x}) p(\mathbf{x})$

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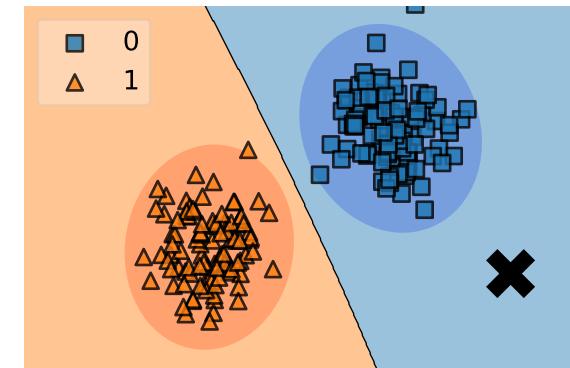


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and  $p(\mathbf{x})$  is low  
= uncertain decision!

Thus, learning the conditional is only a part of the story!  
How can we learn  $p(\mathbf{x})$ ?

# DEEP GENERATIVE MODELING: WHY DO WE NEED THEM?

We clearly see that training a neural network (i.e., a conditional distribution):

$$p(y | \mathbf{x}) = \text{softmax} (\text{NN}(\mathbf{x}))$$

is **not enough!**



Granny Smith	0.1%
iPod	99.7%
library	0.0%
pizza	0.0%
toaster	0.0%
dough	0.0%

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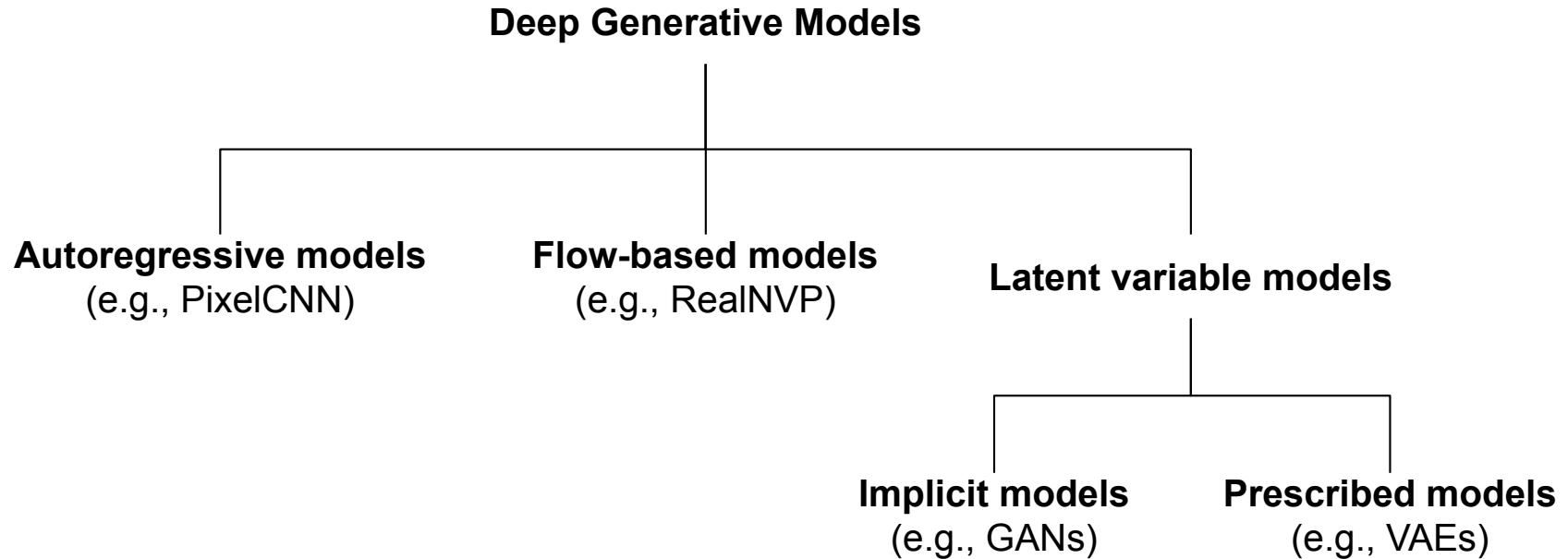
What can we do then?

Or, how to modify the **wrong certainty?**

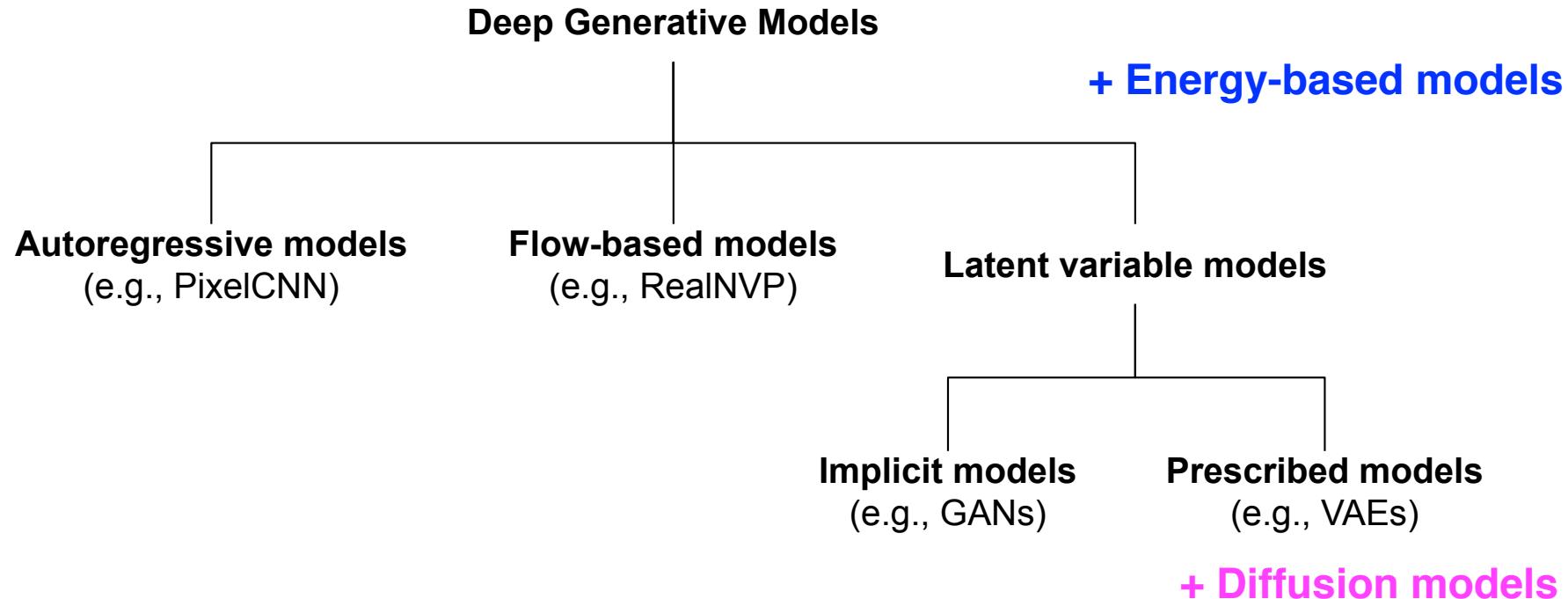


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<b>Generative models</b>	<b>Training</b>	<b>Likelihood</b>	<b>Sampling</b>	<b>Lossy compression</b>	<b>Lossless compression</b>
Autoregressive models	stable	exact	slow	no	yes
Flow-based models	stable	exact	fast/slow	no	yes
Implicit models	unstable	no	fast	no	no
Prescribed model	stable	approximate	fast	yes	no

# DEEP GENERATIVE MODELING: WHERE CAN WE USE IT?

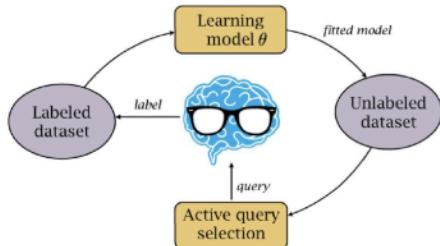
“ i want to talk to you . ”  
“ want to be with you . ”  
“ i do n’t want to be with you . ”  
i do n’t want to be with you .  
she did n’t want to be with him .

---

he was silent for a long moment .  
he was silent for a moment .  
it was quiet for a moment .  
it was dark and cold .  
there was a pause .  
it was my turn .

---

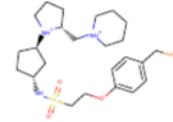
## Text analysis



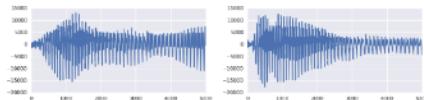
## Active Learning



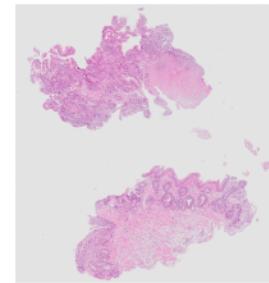
## Image analysis



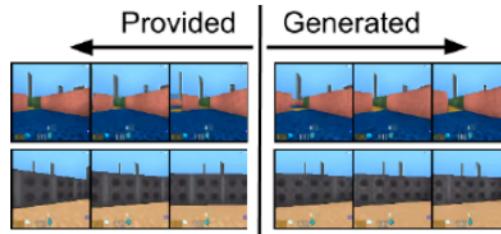
## Graph analysis



## Audio analysis



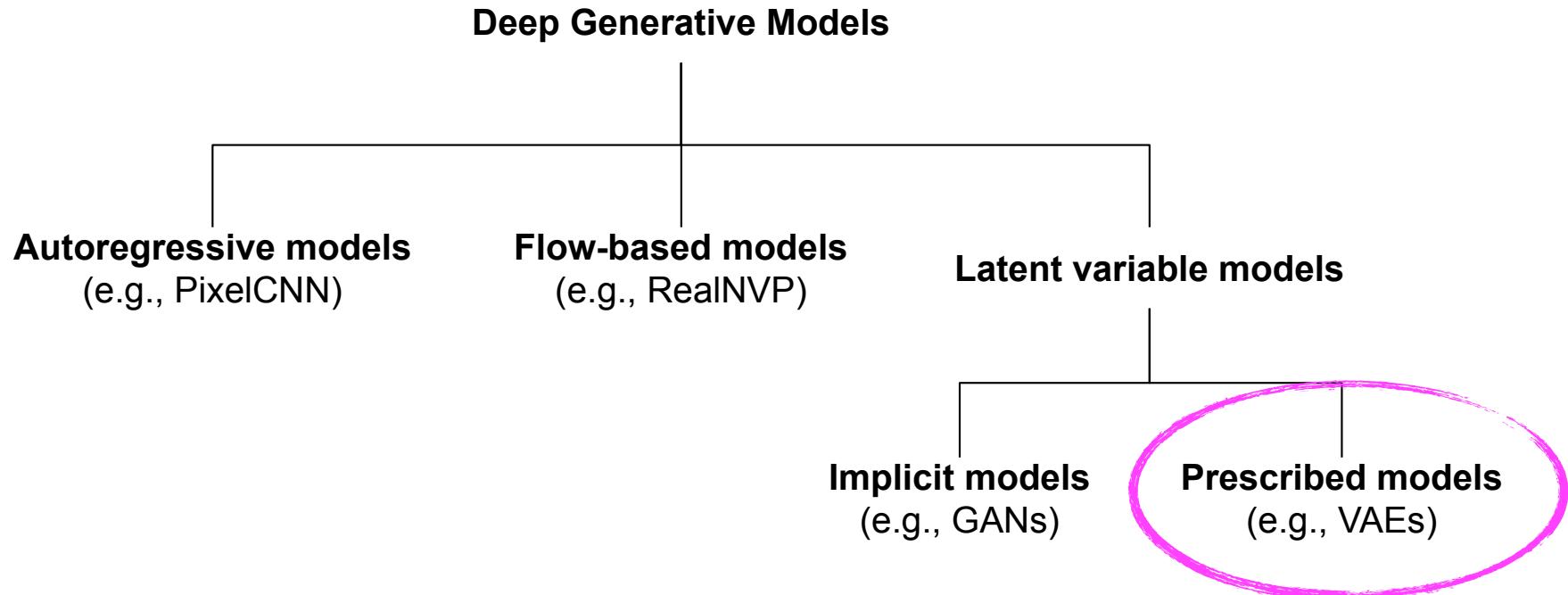
## Medical data



## Reinforcement Learning

and more...

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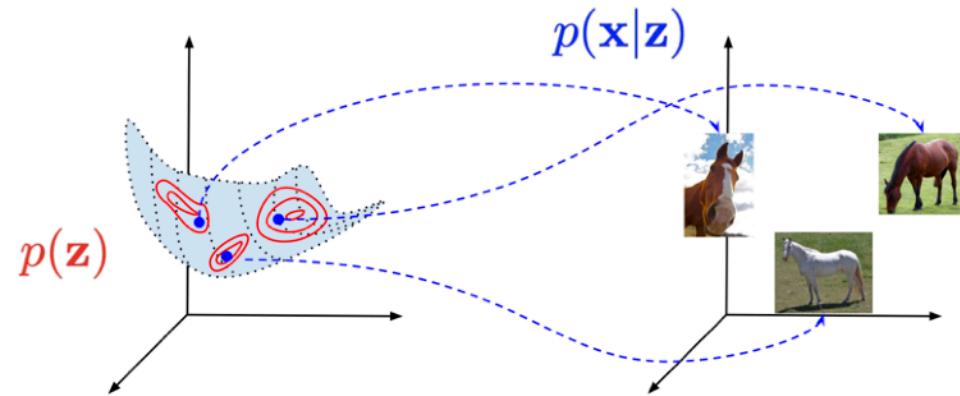


# VARIATIONAL AUTO-ENCODERS

Let's consider a **latent variable model** where we distinguish:

- **latent variables**  $\mathbf{z} \in \mathcal{Z}^M$
- **observable variables**  $\mathbf{x} \in \mathcal{X}^D$

Latent variables lie on a **low-dimensional manifold**.



Generative process:

1.  $\mathbf{z} \sim p(\mathbf{z})$
2.  $\mathbf{x} \sim p(\mathbf{x} | \mathbf{z})$

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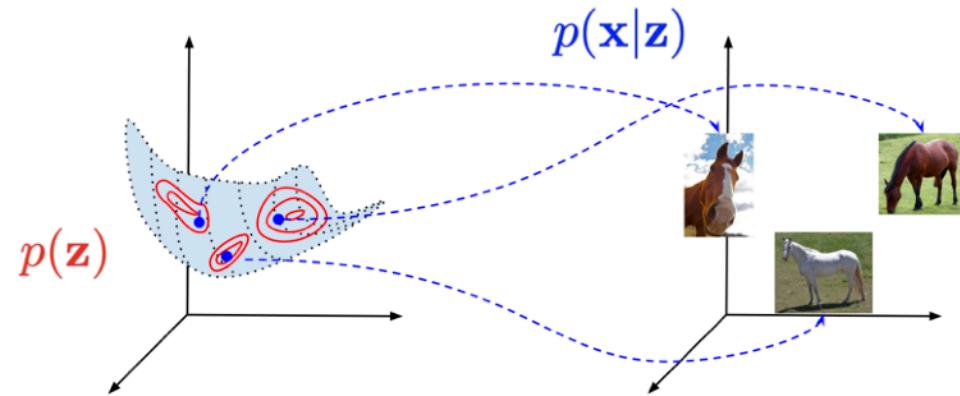
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$$\ln p(\mathbf{x}) = \ln \int p(\mathbf{x} | \mathbf{z}) p(\mathbf{z}) d\mathbf{z}$$



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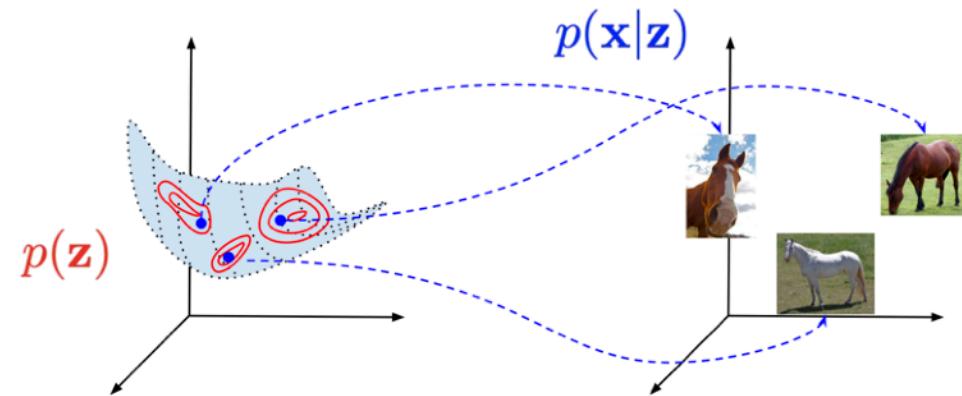
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The integral is intractable...

# VARIATIONAL AUTO-ENCODERS

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Variational posteriors

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$$\begin{aligned}\ln p(\mathbf{x}) &= \ln \int p(\mathbf{x} | \mathbf{z}) p(\mathbf{z}) \, d\mathbf{z} \\&= \ln \int \frac{q_\phi(\mathbf{z})}{q_\phi(\mathbf{z})} p(\mathbf{x} | \mathbf{z}) p(\mathbf{z}) \, d\mathbf{z} \\&= \ln \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z})} \left[ \frac{p(\mathbf{x} | \mathbf{z}) p(\mathbf{z})}{q_\phi(\mathbf{z})} \right] \\&\geq \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z})} \ln \left[ \frac{p(\mathbf{x} | \mathbf{z}) p(\mathbf{z})}{q_\phi(\mathbf{z})} \right] \quad \text{Jensen's inequality} \\&= \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z})} \left[ \ln p(\mathbf{x} | \mathbf{z}) + \ln p(\mathbf{z}) - \ln q_\phi(\mathbf{z}) \right] \\&= \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z})} [\ln p(\mathbf{x} | \mathbf{z})] - \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z})} [\ln q_\phi(\mathbf{z}) - \ln p(\mathbf{z})]\end{aligned}$$

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Reconstruction error “Regularization” term

$$= \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z})} [\ln p(\mathbf{x} | \mathbf{z})] - \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z})} [\ln q_\phi(\mathbf{z}) - \ln p(\mathbf{z})]$$

# VARIATIONAL AUTO-ENCODERS

$$\ln p(\mathbf{x}) \geq \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z}|\mathbf{x})} [\ln p(\mathbf{x}|\mathbf{z})] - \mathbb{E}_{\mathbf{z} \sim q_\phi(\mathbf{z}|\mathbf{x})} [\ln q_\phi(\mathbf{z}|\mathbf{x}) - \ln p(\mathbf{z})]$$

**ELBO: Evidence Lower Bound**

## VARIATIONAL AUTO-ENCODERS

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We consider **amortized inference**:  $q_\phi(\mathbf{z} | \mathbf{x})$

In other words, a single parameterization for each new input  $\mathbf{x}$ .

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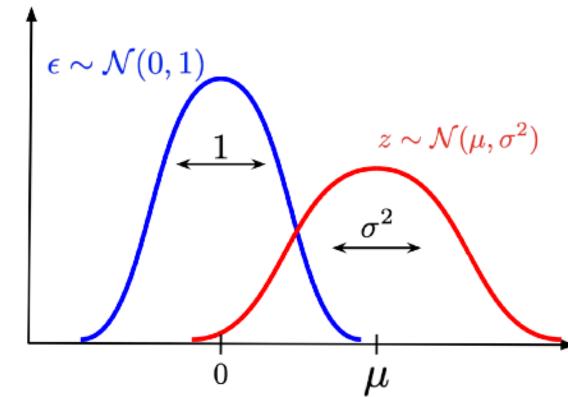
In other words, a single parameterization for each new input  $\mathbf{x}$ .

Moreover, we use **reparameterization trick**:

Every Gaussian variable could be defined as:

$$z = \mu + \sigma \cdot \varepsilon$$

where  $\varepsilon \sim \mathcal{N}(0, 1)$



# VARIATIONAL AUTO-ENCODERS

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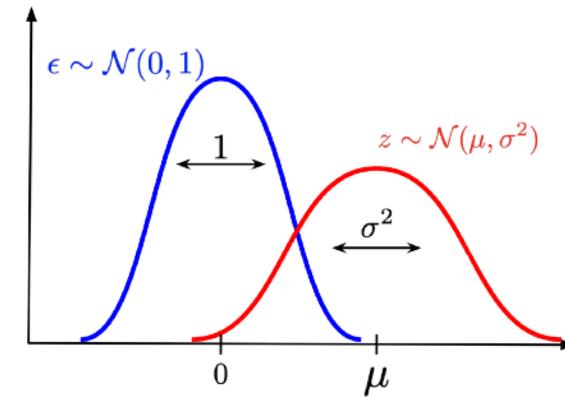
In other words, a single parameterization for each new input  $\mathbf{x}$ .

Moreover, we use **reparameterization trick**:

It reduces the variance of the gradients.

It allows to get randomness outside  $\mathbf{z}$ .

$$z = \mu + \sigma \cdot \epsilon$$

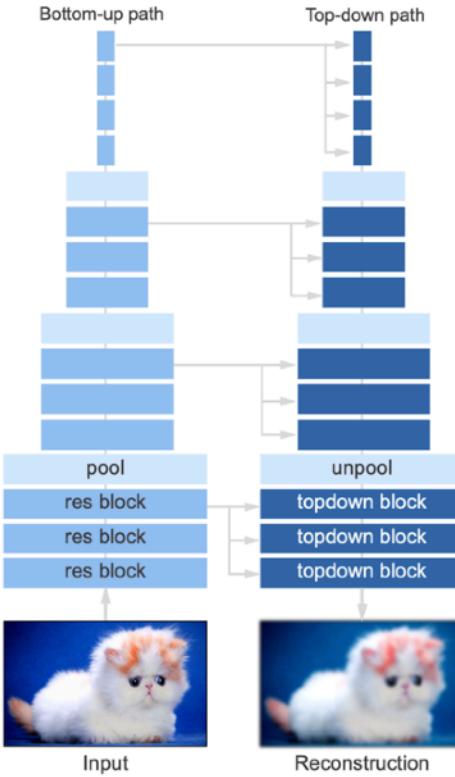


<sup>61</sup> Kingma, D.P., and Welling, M.. "Auto-encoding variational bayes." *ICLR 2014*

# VARIATIONAL AUTO-ENCODERS



Generations



Very Deep VAE

<sup>62</sup> Child, R. "Very Deep VAEs Generalize Autoregressive Models and Can Outperform Them on Images." *ICLR 2021*

# VARIATIONAL AUTO-ENCODERS

i) selfVAE - downscale - 31v1



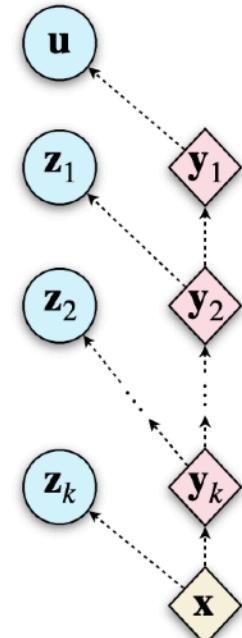
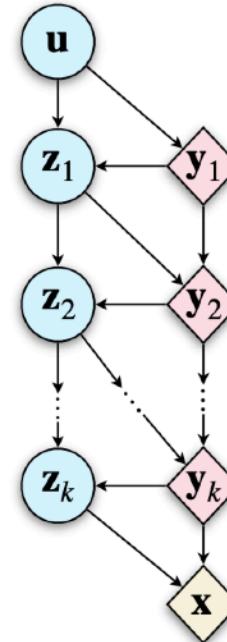
Generations

ii) selfVAE - sketch



i) Generative Model

Hierarchical VAE



# CONCLUSION

- Here: **the likelihood-based generative models.**



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- We **skipped** Generative Adversarial Nets & others.
- Why generative modeling?

$$p(\mathbf{x}, y) = p(y | \mathbf{x}) p(\mathbf{x})$$



# CONCLUSION

- Here: **the likelihood-based generative models.**
- We **skipped** Generative Adversarial Nets & others.
- Why generative modeling?

$$p(\mathbf{x}, y) = p(y | \mathbf{x}) p(\mathbf{x})$$

- Important directions:
  - Better uncertainty quantification
  - New parameterization (new neural networks)
  - Out-of-Distribution
  - Continual learning



# BLOG ABOUT DEEP GENERATIVE MODELING

If you are interested in going deeper into deep generative modeling, please take a look at my blog: [\[Blog\]](#)

- **Intro:** [\[Link\]](#)
- **ARMs:** [\[Link\]](#)
- **Flows:** [\[Link\]](#), [\[Link\]](#)
- **VAEs:** [\[Link\]](#), [\[Link\]](#)
- **Hybrid modeling:** [\[Link\]](#)

# THANK YOU FOR YOUR ATTENTION

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