Mathematics for Machine Learning

— Vector Calculus: Linearization & Multivariate Taylor Series

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Credits for the resource

- The slides are based on the textbooks:
 - Marc Peter Deisenroth, A. Aldo Faisal, and Cheng Soon Ong: Mathematics for Machine Learning. Cambridge University Press. 2020.
 - Howard Anton, Chris Rorres, Anton Kaul: Elementary Linear Algebra. Wiley. 2019.
- We could partially refer to the monograph: Francesco Orabona: A Modern Introduction to Online Learning. https://arxiv.org/abs/1912.13213

Linear Approximation of a Function

The gradient ∇f of a function f can be used for locally linear approximation of f around \mathbf{x}_0 :

$$f(\mathbf{x}) \approx f(\mathbf{x_0}) + (\nabla_{\mathbf{x}} f)(\mathbf{x_0})(\mathbf{x} - \mathbf{x_0})$$

• $(\nabla_{\mathbf{x}} f)(\mathbf{x}_0)$: the gradient of f w.r.t. \mathbf{x} evaluated at \mathbf{x}_0 .

Multivariate Taylor Series

Multivariate Taylor Series

Consider a function $f: \mathbb{R}^D \mapsto \mathbb{R}$ which is smooth (i.e., infinitely differentiable) at \mathbf{x}_0 .

Define the different vector $\delta := \mathbf{x} - \mathbf{x}_0$.

The multivariate Taylor series of f at x_0 is

$$f(\mathbf{x}) = \sum_{k=0}^{\infty} \frac{D_{\mathbf{x}}^{k} f(\mathbf{x}_{0})}{k!} \delta^{k},$$

where $D_{\mathbf{x}}^{k} f(\mathbf{x}_{0})$ is the kth derivative of f w.r.t. \mathbf{x} evaluated at \mathbf{x}_{0} .

Multivariate Taylor Polynomial

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The Taylor polynomial of degree n of f at x_0 is

$$T_n(\mathbf{x}) = \sum_{k=0}^n \frac{D_{\mathbf{x}}^k f(\mathbf{x}_0)}{k!} \delta^k,$$

where $D_{\mathbf{x}}^{k} f(\mathbf{x}_{0})$ is the kth derivative of f w.r.t. \mathbf{x} evaluated at \mathbf{x}_{0} .

• It contains the first n+1 components of the Taylor series.

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- $oldsymbol{\delta}^2 := oldsymbol{\delta} \otimes oldsymbol{\delta} = oldsymbol{\delta} oldsymbol{\delta}^{ op}.$
 - $\delta^2[i,j] = \delta[i]\delta[j]$.
- $\delta^3 := \delta \otimes \delta \otimes \delta$.
 - $\delta^3[i,j,k] = \delta[i]\delta[j]\delta[k]$.

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- Hence,

$$D_{\mathbf{x}}^k f(\mathbf{x}_0) \boldsymbol{\delta}^k = \sum_{i_1=1}^D \cdots \sum_{i_k=1}^D D_{\mathbf{x}}^k f(\mathbf{x}_0) [i_1, \dots, i_k] \delta[i_1] \cdots \delta[i_k].$$



Note & Exercise

Exercise

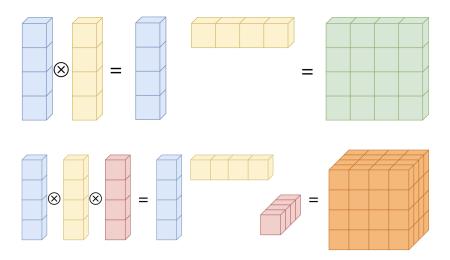
Show that

$$D_{\mathbf{x}}^2 f(\mathbf{x}_0) \delta^2 = \delta^{\top} \mathbf{H}(\mathbf{x}_0) \delta,$$

where

$$\boldsymbol{H} = \begin{bmatrix} \frac{\partial^2 f}{\partial x^2} & \frac{\partial^2 f}{\partial x \, \partial y} \\ \frac{\partial^2 f}{\partial y \, \partial x} & \frac{\partial^2 f}{\partial y^2} \end{bmatrix}.$$

$$\delta^2 \& \delta^3$$



Example

Consider the function $f(x,y) = x^2 + 2xy + y^3$ and $(x_0, y_0) = (1,2)$.

• Note: f is a polynomial of degree 3.

$$f(1,2) = 13, \quad \delta = [x-1, y-2]^{\top}.$$

$$\frac{\partial f}{\partial x} = 2x + 2y \Longrightarrow \frac{\partial f}{\partial x}(1,2) = 6.$$

$$\frac{\partial f}{\partial y} = 2x + 3y^2 \Longrightarrow \frac{\partial f}{\partial y}(1,2) = 14.$$

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$$\implies \frac{D_{x,y}^1 f(1,2)}{1!} \delta = \begin{bmatrix} 6 & 14 \end{bmatrix} \begin{bmatrix} x-1 \\ y-2 \end{bmatrix} = 6(x-1) + 14(y-2).$$

Example

$$\frac{\partial^2 f}{\partial x^2} = 2 \implies \frac{\partial^2 f}{\partial x^2} (1, 2) = 2$$

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$$\Rightarrow H(1,2) = \begin{bmatrix} 2 & 2 \\ 2 & 12 \end{bmatrix} \in \mathbb{R}^{2 \times 2}.$$

$$\frac{D_{x,y}^2 f(1,2)}{2!} \boldsymbol{\delta}^2 = \frac{1}{2} \boldsymbol{\delta}^\top \boldsymbol{H}(1,2) \boldsymbol{\delta}$$
$$= \cdots$$

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$$\frac{D_{x,y}^2 f(1,2)}{2!} \boldsymbol{\delta}^2 = \frac{1}{2} \boldsymbol{\delta}^\top \boldsymbol{H}(1,2) \boldsymbol{\delta}$$
$$= \cdots = (x-1)^2 + 2(x-1)(y-2) + 6(y-2)^2.$$

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Check if
$$f(x) = f(1,2) + D_{x,y}^1 f(1,2) \delta + \frac{D_{x,y}^2 f(1,2)}{2!} \delta^2 + \frac{D_{x,y}^3 f(1,2)}{3!} \delta^3$$
.

Discussions