Advanced Math Notes

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Contents

1 Free parameter

A variable in a mathematical model which cannot be predicted precisely or constrained by the model and must be estimated experimentally or theoretically.

2 Rectifier

2.1 Definition

An activation function defined as the positive part of its argument:

$$f(x) = \max(0, x)$$

Also known as: ramp function
A unit employing the rectifier is also called a **rectified linear unit (ReLU)**

2.2 Softplus

A smooth approximation to the rectifier is the analytic function

$$f(x) = \log(1 + e^x)$$

Also known as: SmoothReLU
The derivative of softplus is

$$f'(x) = \frac{1}{1 + e^{-x}}$$

(the logistic function)

Notes The logistic function is a smooth approximation of the derivative of the rectifier, the **Heaviside step function**

2.3 Multivariable Generalization to Softplus

LogSumExp with the first argument set to zero

$$LSE_0^+(x_1, \dots, x_n) := LSE(0, x_1, \dots, x_n) = \log(1 + e^{x_1} + \dots + e^{x_n})$$

Notes The LogSumExp function itself is:

$$LSE(x_1, \ldots, x_n) = \log(e^{x_1} + \ldots + e^{x_n})$$

and its gradient is the softmax.
The softmax with the first argument set to zero is the multivariable generalization of the logistic function.

3 Softmax Function

The softmax function takes an un-normalized vector, and normalizes it into a probability distribution. That is, prior to applying softmax, some vector elements could be negative, or greater than one; and might not sum to 1; but after applying softmax, each element x_i is in the interval $[0, 1]$, and $\sum_i x_i = 1$

$$\sigma : \mathbb{R}^K \to \{\sigma \in \mathbb{R}^K | \sigma_i > 0, \sum_{i=1}^{K} \sigma_i = 1\}$$

$$\sigma(\mathbf{z})_j = \frac{e^{z_j}}{\sum_{k=1}^{K} e^{z_k}}$$

for $j = 1, \ldots, K$

4 Cross Product in Higher Dimensions

A way of turning 3 vectors in 4-space into a fourth vector, orthogonal to the others, in a trilinear way
Canonical basis of $\mathbb{R}^4$: (e_1, e_2, e_3, e_4). If your vectors are $\mathbf{t} = (t_1, t_2, t_3, t_4)$, $\mathbf{u} = (u_1, u_2, u_3, u_4)$ and $\mathbf{v} = (v_1, v_2, v_3, v_4)$, then compute the determinant:

$$\begin{vmatrix} t_1 & t_2 & t_3 & t_4 \\ u_1 & u_2 & u_3 & u_4 \\ v_1 & v_2 & v_3 & v_4 \\ e_1 & e_2 & e_3 & e_4 \end{vmatrix}$$

The cross product of $\mathbf{t}, \mathbf{u}, \mathbf{v}$ is:

$$-e_1 \begin{vmatrix} t_2 & t_3 & t_4 \\ u_2 & u_3 & u_4 \\ v_2 & v_3 & v_4 \end{vmatrix} + e_2 \begin{vmatrix} t_1 & t_3 & t_4 \\ u_1 & u_3 & u_4 \\ v_1 & v_3 & v_4 \end{vmatrix} - e_3 \begin{vmatrix} t_1 & t_2 & t_4 \\ u_1 & u_2 & u_4 \\ v_1 & v_2 & v_4 \end{vmatrix} + e_4 \begin{vmatrix} t_1 & t_2 & t_3 \\ u_1 & u_2 & u_3 \\ v_1 & v_2 & v_3 \end{vmatrix}$$