# Foundations of Machine Learning Al2000 and Al5000

FoML-05 Maximum A Posteriori Fully Bayesian treatment

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#### So far in FoML

- What is ML and the learning paradigms
- Probability refresher
- Maximum Likelihood Principle









Given - Dataset of N independent observations D





Given - Dataset of N independent observations D

ML estimate - w that maximizes the data likelihood

$$\mathbf{w}_{ML} = \underset{w}{\text{arg wex}} P(D|w)$$





• Given - Dataset of N independent observations D =  $\left\{ \begin{array}{c} u_1 & u_2 \end{array} \right\}$ 

• MAP estimate - choose most probable w given data





Given - Dataset of N independent observations D

MAP estimate - choose most probable w given data

$$\mathbf{w}_{MAP} = \frac{\mathbf{w}_{max}}{\mathbf{w}} \qquad P(\mathbf{w}_{D})$$





• Given data D  $D = \{(x_1, t_1), (x_2, t_2), \dots (x_N, t_N)\} = \{\mathbf{x}, \mathbf{t}\}$ 





Given data D

$$D = \{(x_1, t_1), (x_2, t_2), \dots (x_N, t_N)\} = \{\mathbf{x}, \mathbf{t}\}$$

Model

$$p(t|x,\mathbf{w},\beta) = \mathcal{N}(t|y(x,\mathbf{w}),\beta^{-1}) = \sqrt{\frac{\beta}{2}} e^{-\frac{\beta}{2}(t-y|x,\omega)}$$





Given data D

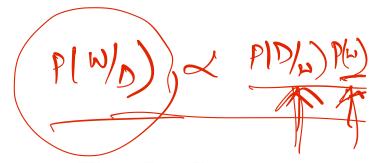
$$D = \{(x_1, t_1), (x_2, t_2), \dots (x_N, t_N)\} = \{\mathbf{x}, \mathbf{t}\}$$

ullet Model  $p(t|x,\mathbf{w},eta) = \mathcal{N}(t|y(x,\mathbf{w}),eta^{-1})$ 

$$\mathbf{w}_{MAP} = \underset{\mathbf{w}}{\operatorname{arg\,max}} p(\mathbf{w}|\mathbf{x}, \mathbf{t}, \beta)$$







Given data D

$$D = \{(x_1, t_1), (x_2, t_2), \dots (x_N, t_N)\} = \{\mathbf{x}, \mathbf{t}\}$$

Model

$$p(t|x, \mathbf{w}, \beta) = \mathcal{N}(t|y(x, \mathbf{w}), \beta^{-1})$$

$$\mathbf{w}_{MAP} = \underset{\mathbf{w}}{\operatorname{arg\,max}} p(\mathbf{w}|\mathbf{x}, \mathbf{t}, \beta)$$

Given a prior  $\mathcal{P}(\omega \bowtie)$  the posterior distribution becomes

$$p(\mathbf{w}|\mathbf{x},\mathbf{t},\beta,\alpha) = \frac{P(\mathsf{t}|\mathbf{w},\mathsf{x},\beta) P(\mathbf{w}|\mathbf{x})}{P(\mathsf{t}|\mathbf{x},\beta,\alpha)}$$



P(HX,N,B) P(W/A)



MAP estimate - for convenience apply log

$$\mathbf{w}_{MAP} = \underset{\omega}{\operatorname{argmax}} \left[ \log P(\frac{t}{x}, \omega, \beta) + \log P(\omega|\alpha) - \log P(\frac{t}{x}, \beta, \alpha) \right]$$
in dependent  $\mathfrak{g}^{\omega}$ 



 $i = \{1, 2...m\}$ 

ullet Assuming Gaussian Prior and independence on parameters  $\mathbf{w} \in \mathbb{R}^{\mathbf{M}}$ 

$$p(\mathbf{w}|\alpha) = \prod_{i=1}^{M} \mathcal{N}(\mathbf{w}_{i}|\mathbf{0}, \alpha^{-1}) = \prod_{i=1}^{M} \underbrace{\frac{d}{2\pi}}_{i=1} e^{-\frac{d}{2}} \underbrace{\omega_{i}^{2}}_{i=1} = \underbrace{\frac{d}{2\pi}}_{i=1} \underbrace{\frac{d}{2\pi}}_{i=1}$$



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 $\mathbf{w_{MAP}} = \arg\min - \log \mathbf{p}(\mathbf{w}|\mathbf{x}, \mathbf{t}, \beta, \alpha) = \arg\min - \log \mathbf{p}(\mathbf{t}|\mathbf{x}, \mathbf{w}, \beta) - \log \mathbf{p}(\mathbf{w}|\alpha)$ = organin - log P(Hx,w,B) - log ((Z) M2 - ZWTW) argmin  $-\log P[t|x,w,B] - \frac{M}{2} \log \frac{\pi}{2\pi} + \frac{\pi}{2} w^{T}w$   $\lim_{i=1}^{R} \frac{-B}{2\pi} \left[ t_{i} - y(x_{i},w) \right] \qquad \lim_{i=1}^{R} \lim_{i=1}^{R} \frac{W^{T}w}{2\pi} \right]$ arg min  $\left( \frac{B}{2} \right) = \frac{1}{2\pi} \left[ \frac{1}{2\pi} - \frac{1}{2\pi} \left( \frac{1}{2\pi} \right) \right] + \frac{1}{2\pi} w^{T}w$   $\lim_{i=1}^{R} \frac{W^{T}w}{2\pi} = \frac{1}{2\pi} \left[ \frac{1}{2\pi} - \frac{1}{2\pi} \left( \frac{1}{2\pi} \right) \right] + \frac{1}{2\pi} w^{T}w$ భారతీయ సాంకేతిక విజ్జాన సంస్థ హైదరాబాద్

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Predictive distribution

$$P(t'|x',\beta) = \mathcal{N}(t'|y(w_{MAD}x_i),\beta)$$

point estimate t = y(Wmap, x')





## Bayesian Prediction





#### So far

- Our estimates for w have been point estimates
  - ML and MAP





#### So far

- Our estimates for w have been point estimates
  - o ML and MAP
  - o Regarded as frequentist because they discard 'uncertainty' about the w





 An approach that relies on consistent application of sum and product rules of probability at all levels of modeling





• Given a prior belief  $p(\mathbf{w}|\alpha)$  over w, and data D





- Given a prior belief  $p(\mathbf{w}|\alpha)$  over w, and data D
- We are interested in the posterior

$$p(\mathbf{w}|\mathbf{D}) = \frac{P(\mathcal{D}/w) P(w)}{P(\mathcal{D})}$$





The predictive distribution becomes

$$p(x'|D) = \int P(x',w|D) dw = \int P(x'|D) dw$$





• Curve fitting example





- Curve fitting example
- Given training data (x, t)





- Curve fitting example
- Given training data (x, t) and a test sample x





- Curve fitting example
- Given training data (x, t) and a test sample x
- Goal predict the value of t





- Curve fitting example
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M(H/N/F)

We wish to evaluate the predictive distribution

$$p(t|x, \mathbf{x}, \mathbf{t})$$





W~ N(0, 1)

$$p(t|x,\mathbf{x},\mathbf{t}) = \int p(t|x,\mathbf{w})p(\mathbf{w}|\mathbf{x},\mathbf{t}) d\mathbf{w}.$$

$$= \int P(t,\mathbf{w}/\mathbf{x},\mathbf{x},t) d\mathbf{w}$$

$$= \int P(t/\mathbf{x},\mathbf{x},t) d\mathbf{w}$$

$$= \int P(t/\mathbf{x},\mathbf{w}) P(-\mathbf{w}/\mathbf{x},\mathbf{x},t) d\mathbf{w}$$

$$= \int P(t/\mathbf{x},\mathbf{w}) P(-\mathbf{w}/\mathbf{x},\mathbf{x},t) d\mathbf{w}$$



భారతీయ సాంకేతిక విజ్ఞాన సంస్థ హైదరాబాద్ भारतीय प्रौद्योगिकी संस्थान हैदराबाद Indian Institute of Technology Hyderabad Data-driven Intelligence & Learning Lab

- Advantages
  - Inclusion of the prior knowledge
  - o Represents uncertainty in t' due to the target noise and uncertainty over w





- Advantages
  - Inclusion of the prior knowledge
  - Represents uncertainty in t' due to the target noise and uncertainty over w
- Disadvantages
  - Posterior is hard to compute analytically
  - Prior is often a mathematical convenience





## Rough work





# Next Linear Models - Regression



