

GP

Description: This class uses preference, coac, and ordinal feedback to maintain a Bayesian posterior via a Gaussian process.

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Class Details

Superclasses [handle](#)

Sealed false

Construct on load false

Constructor Summary

[GP](#) Construct an instance of this class

Property Summary

GP_noise_var	hyperparameter for noise variance of the GP
action_names	
actions	over which to evaluate posterior
coac_data	
coac_labels	
coac_noise	
grid_size	grid size corresponding to continuous action space
initial_guess	
isNormalize	option to normalize posterior to 0 to 1
lengthscales	hyperparameter for lengthscale of each action space dimension
linkfunction	
mean	
ord_data	
ord_labels	
ord_noise	
ordinal_thresholds	
pref_data	
pref_labels	
pref_noise	posterior noise hyperparameter for:
prior_cov	
prior_cov_inv	
sigma	
signal_variance	hyperparameter for mean variance of the GP
uncertainty	

Method Summary

addlistener	Add listener for event.
delete	Delete a handle object.
eq	== (EQ) Test handle equality.

	findobj	Find objects matching specified conditions.
	findprop	Find property of MATLAB handle object.
	ge	>= (GE) Greater than or equal relation for handles.
	gt	> (GT) Greater than relation for handles.
Sealed	isvalid	Test handle validity.
	le	<= (LE) Less than or equal relation for handles.
	listener	Add listener for event without binding the listener to the source object.
	lt	< (LT) Less than relation for handles.
	ne	~= (NE) Not equal relation for handles.
	notify	Notify listeners of event.
	plotGP	Description: Plots the posterior mean
Static	sigmoid	Evaluates the sigmoid function at x
Static	sigmoid_der	Evaluates the derivative of the sigmoid function at x
Static	sigmoid_der2	Evaluates the 2nd derivative of the sigmoid function at x

Event Summary

ObjectBeingDestroyed	Notifies listeners that a particular object has been destroyed.
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