

**BRAC UNIVERSITY**  
**Department of Computer Science and Engineering**

Examination: Final  
Duration: 90 minutes

Semester: Spring 2025  
Full Marks: 30

**CSE 440: Natural Language Processing II**

Figures in the right margin indicate marks.

**Answer all 3**

1.   A. You need to assign PoS tags for the sentence **I love good movies**. You only [6]  
have four tags: noun (NN), verb (VB), adjective (ADJ) and pronoun (PN).  
During your training of an HMM, it learns these emission probability and tag  
transition probability matrices (appendix A: on the other side). Using the  
Viterbi algorithm, calculate the Viterbi values for **love** (i.e. fill up the second  
column).  
  
      B. Write the three approximations Hidden Markov Models use for PoS tagging. [4]  
Write two disadvantages of Hidden Markov Model PoS taggers.
2.   A. Write short notes (equation, graph characteristics, advantages, [6]  
disadvantages) on these three activation functions:  
      a. Leaky ReLU  
      b. Sigmoid  
      c. TanH  
  
      B. Calculate the updated cell state vector of an LSTM unit for the provided data [4]  
given in Appendix B (on the other side).
3.   A. Write the process of attention based Seq2seq RNN translation model. [4]  
  
      B. Complete two full iteration of EM algorithm on the given language: [6]  
           $a\ b\ c \rightarrow x\ y\ z$   
           $a \rightarrow x$   
           $b \rightarrow z$

## Appendix A:

A:

	NN	VB	PN	ADJ
<s>	0.3	0.2	0.4	0.1
NN	0.05	0.7	0.15	0.1
VB	0.1	0.05	0.1	0.75
PN	0.05	0.70	0.1	0.15
ADJ	0.8	0.1	0.1	0

B:

	I	good	love	movies
NN	0.1	0.1	0.1	0.7
VB	0.1	0	0.8	0.1
PN	0.9	0.1	0	0
ADJ	0	0.8	0.2	0

## Appendix B:

Equations:

$$f_t = \sigma(W_f x_t + U_f h_{t-1} + b_f)$$

$$i_t = \sigma(W_i x_t + U_i h_{t-1} + b_i)$$

$$\hat{C}_t = \tanh(W_c x_t + U_c h_{t-1} + b_c)$$

$$C_t = f_t * C_{t-1} + i_t * \hat{C}_t$$

Matrices:

$$W_f = [1 \ 0, \ 0 \ 1]$$

$$U_f = [1 \ 1, \ 2 \ 2]$$

$$b_f = [1 \ 1]^T$$

$$W_i = [0 \ 1, \ 1 \ 0]$$

$$U_i = [1 \ 0, \ 0 \ 4]$$

$$b_i = [0 \ 0]^T$$

$$W_c = [1 \ 3, \ 0 \ 1]$$

$$U_c = [1 \ 4, \ 0 \ 0]$$

$$b_c = [1 \ 0]^T$$

$$x_t = [2 \ 1]^T$$

$$h_{t-1} = [4 \ 1]^T$$