A Sample Quarto Document

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The following is a sample Quarto document which highlights several autoring features. This page was mainly created for my own reference. I use a recent lecture note as a base to edit off of.

## Cool features

(Test)… here is a theorem:

|  |  |
| --- | --- |
|  | **Theorem 1 (Line)** The equation of any straight line, called a linear equation, can be written as: |

## Topics

* Modern DL methods for learning across tasks
* Implementing these methods (MT, TL) in PyTorch
* Glimpse of building new algorithms

low-level descriptions:

* MT, TL
* Meta learning algos
* Advanced meta learning topics
* Unsupervised pre-training
  + FS learning
* Domain adaption
* Lifelong learning
* Open problems

Focus on DL, with case studies in things like NLP. - No RL! (see CS 224R)

## 1. Logistics

* Lectures are live-streamed and recorded
* two guest lectures
* Prereqs:
  + Sufficient background in ML (229)

### Homeworks

50% of grade.

* 0: multi-task basics
* 1: multi-task data processing and BB-ML
* 2: gradient-based ML
* 3: fine-tuning pre-trained language models
* 4 (optional): Bayesian ML and meta overfitting
  + Replace 15% of hw/project
  + Not coding, all math
* 6 late days

### Project

Here is a footnote reference,[[1]](#footnote-27) and another.[[2]](#footnote-28)

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Here is a bib citation. Blah Blah [see @knuth1984, pp. 33-35; also @wickham2015, chap. 1]

* Poster session, 50% of grade.
* Idea: …

Now technical content…

## 2. Why study multi-task learning and meta-learning?

* How can we enable agents to learn a breadth of skills in the real world?
  + Because each time we have to train a supervised signal
    - So the goal is to learn representations across tasks
* Aside (common paradigm to learn representations): initialize well (not randomly) –> fine-tune on new task.
  + This is harder for RL than NLP because NLP has the entire wikipedia to use but robotic common sense representations are not as straightforward (maybe we need a common robot embedding?)

**Evolution**:

* Early in CV: hand-design features, train SVM on-top
* Modern CV: end-to-end training, no hand-engineering
  + Allows us to handle unstructured inputs without understanding it
* Now why meta-learning? Three reasons…
  + **Don’t have large dataset** at the outset to pre-train on or use in end-to-end SL manner (med imaging, robotics, etc.)
    - Even more so: **long-tail data** samples (e.g., self-driving won’t catch all edge cases)
      * MEL techniques can help with this (kinda… not the main focus tho)
  + **Quickly learn something new** (few-shot learning)
* Lots of open problems

## Multi-task intro

Some code block:

print(5)

* What is a task? See [Theorem 1](#thm-line).
  + Dataset + loss objective –> model
  + Objects as “tasks”
  + Critical assumption: different tasks need to share some base structure (goal is to exploit shared structure)
    - But lots of tasks share structure (even as upstream as sharing the laws of physics!)
    - Question: can we learn a shared embedding space for e.g., text + images in one?
* Does MT learning reduce to single-task SL learning?
  + Somewhat (tho not for every problem)
  + Idea: sum loss and data:

Next up: a technical dive into the **multi-task** learning framework.

## Acknowledgments

I am grateful for the insightful comments offered by the anonymous peer reviewers at Books & Texts. The generosity and expertise of one and all have improved this study in innumerable ways and saved me from many errors; those that inevitably remain are entirely my own responsibility.

1. Here is the footnote. [↑](#footnote-ref-27)
2. Here’s one with multiple blocks.

   Subsequent paragraphs are indented to show that they belong to the previous footnote.

   { some.code }

   The whole paragraph can be indented, or just the first line. In this way, multi-paragraph footnotes work like multi-paragraph list items. [↑](#footnote-ref-28)