

$m$  } Finish Factor Analysis  
 PCA

A little behind our planned PACE

But well within Buffer!

PLEASE KEEP Questions Coming

### Factor Analysis RECAP

$$x^{(1)}, \dots, x^{(n)} \in \mathbb{R}^d$$

Recall: MANY fewer points than dimensions "n < d"

think about: 1000 sensors measured for some small # of days

Key IDEA: LATENT STRUCTURE IN R.V. (constraints degree of freedom)

### Recall likelihood function

$$l(\mu, \Sigma) = \sum_{i=1}^n \log \frac{1}{2\pi |\Sigma|^{\frac{1}{2}}} \exp \left\{ -\frac{1}{2} (x^{(i)} - \mu)^T \Sigma^{-1} (x^{(i)} - \mu) \right\}$$

$$= \sum_{i=1}^n -\frac{1}{2} (x^{(i)} - \mu)^T \Sigma^{-1} (x^{(i)} - \mu) - \log 2\pi |\Sigma|^{\frac{1}{2}}$$

Hence equivalent to look at

$$g(\mu, \Sigma) = \sum_{i=1}^n (x^{(i)} - \mu)^T \Sigma^{-1} (x^{(i)} - \mu) + \log |\Sigma| + \log 2\pi$$

WE'LL REASON ABOUT STRUCTURE IN  $\Sigma$

Recall: If  $\text{RANK}(\Sigma) \leq n < d$ , many problems:  $\Sigma^{-1}$  is not defined

$$|\Sigma| = 0$$

Estimate: if  $\Sigma$  is full rank, easy to estimate  $\mu$ .

$\sim$

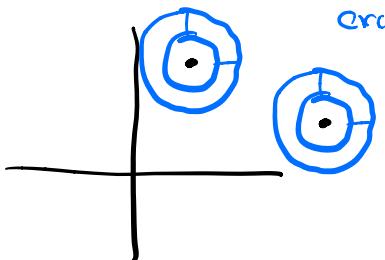
$$\nabla_{\mu} g(\mu, \Sigma) = 2 \sum_{i=1}^n (\mathbf{x}^{(i)} - \mu) = 0 \quad (\text{critical points})$$

$$\Leftrightarrow \Sigma \left( \sum_{i=1}^n (\mathbf{x}^{(i)} - \mu) \right) = 0 \quad (\text{full rank})$$

$$\Rightarrow \mu = \frac{1}{n} \sum_{i=1}^n \mathbf{x}^{(i)} \quad \text{ESTIMATE } \mu$$

$\therefore \mu$  is EASY TO ESTIMATE whenever  $\Sigma$  is full rank

Building Block 1  $\Sigma = \sigma^2 I$   $\sigma^2$  is just a scalar



CIRCULAR COVARIANCE

How many free parameters?

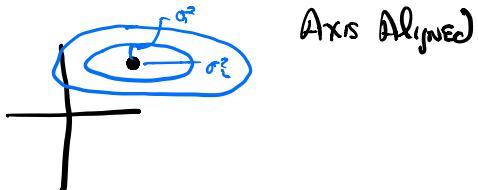
$$\Rightarrow 1 \text{ vs } \Sigma (\sigma^2)$$

$$\text{Last time} \quad \sigma^2 = \frac{1}{nd} \sum_{i=1}^n \|(\mathbf{x}^{(i)} - \mu)\|^2$$

ESTIMATE  $\sigma^2$  BY SUBTRACTING MEAN, SQUARING EACH

Building Block #2

$$\Sigma = \begin{bmatrix} \sigma_1^2 & 0 \\ 0 & \sigma_n^2 \end{bmatrix}$$



Axis Aligned

$$g(\mu, \Sigma) = \sum_{i=1}^n (\mathbf{x}^{(i)} - \mu)^T \Sigma^{-1} (\mathbf{x}^{(i)} - \mu) + \log |\Sigma|$$

$$|\Sigma| = \prod_{j=1}^d \sigma_j^2$$

$$(z_i = \sigma_i^2) = \sum_{i=1}^n \sum_{j=1}^d z_j^{-1} (\mathbf{x}_{ij} - \mu_j)^2 + \log z_i$$

Decouples into  $d$  problems.

$$\text{fix } j \quad \sum_{i=1}^n z_j^{-1} (\mathbf{x}_{ij} - \mu_j)^2 + \log z_i$$

$$\sigma_j^2 = \frac{1}{n} \sum_{i=1}^n (x_j^{(i)} - \mu_j)^2 \quad 1d \text{ Gaussians}$$

∴ if we assume this Axis-Aligned Structure, we can also fit its components

### Our Factor Model

#### PARAMETERS

**Fit**

$$\begin{cases} \mu \in \mathbb{R}^d & s < d \text{ "small dim"} \\ \Lambda \in \mathbb{R}^{d \times s} \\ \Phi \in \mathbb{R}^{d \times d} \end{cases} \quad - \text{Diagonal matrix}$$

#### MODEL

$$P(X, Z) = P(X | Z) P(Z) \quad Z \text{ is LATENT VARIABLE}$$

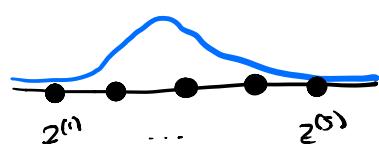
$$Z \sim N(0, I) \in \mathbb{R}^s \quad \text{for } s < d$$

$$X = \underbrace{\mu}_{\text{MEAN}} + \underbrace{\Lambda Z}_{\text{MAP from small dims to high dim}} + \epsilon \quad \text{or } X \sim N(\mu + \Lambda Z, \Phi)$$

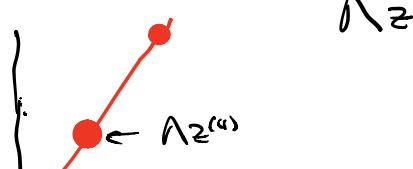
$$\epsilon \sim N(0, \Phi) \quad \text{noisy.}$$

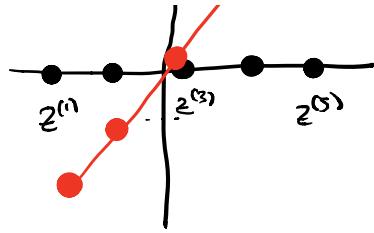
Ex:  $d=2, s=1, n=5 : X = \mu + \Lambda Z + \epsilon$

1. GENERATE  $Z^{(1)}, \dots, Z^{(s)}$  from  $N(0, I)$

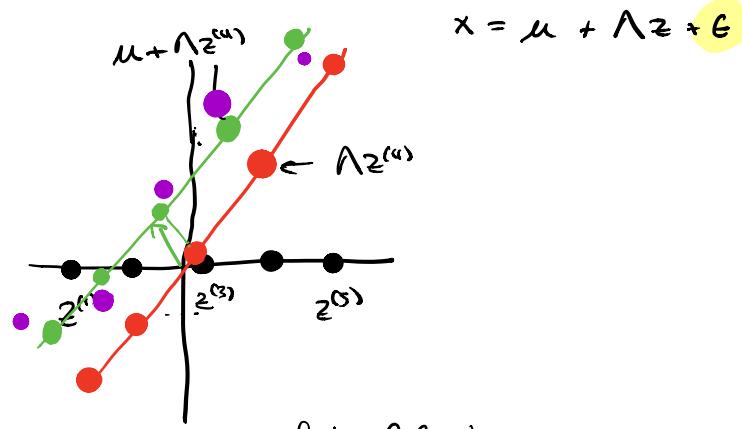


2.  $\Lambda = \begin{bmatrix} 1 \\ z \end{bmatrix}$





3. Abbau



$$x = \mu + \Lambda z + \epsilon$$

Finally we can sample which full dimensional

Model is clear: Small dim  $\rightarrow$  large dim

### TECHNICAL TOOLS Block Gaussians

$$\mathbf{x} = \begin{bmatrix} \mathbf{x}_1 \\ \mathbf{x}_2 \end{bmatrix} \quad \mathbf{x}_1 \in \mathbb{R}^{d_1}, \quad \mathbf{x}_2 \in \mathbb{R}^{d_2}, \quad \mathbf{x} \in \mathbb{R}^{d_1+d_2}$$

$$\Sigma = \begin{bmatrix} d_1 & d_2 \\ \Sigma_{11} & \Sigma_{12} \\ \Sigma_{21} & \Sigma_{22} \end{bmatrix} \left| \begin{array}{l} d_1 \\ d_2 \end{array} \right. \quad \Sigma_{ij} \in \mathbb{R}^{d_i \times d_j} \quad i, j \in \{1, 2\}$$

Fact 1:  $P(x_1) = \int_{x_2} P(x_1, x_2)$  MARGINALIZATION  
For GAUSSIANS,  $P(x_1) = N(\mu_{11}, \Sigma_{11})$  GAUSSIAN

Fact 2:  $P(x_1 | x_2) \sim N(\mu_{1|2}, \Sigma_{1|2})$  conditions  
 $\mu_{1|2} = \mu_1 + \Sigma_{12} \Sigma_{22}^{-1} (x_2 - \mu_2)$

MATRIX INVERSION

$$\hat{\Sigma}_{11|2} = \Sigma_{11} - \Sigma_{12} \Sigma_{22}^{-1} \Sigma_{11}$$

Lemma

Summary: Learned about block notation

↳ we say Gaussians are closed under

marginalization & conditioning.

## Factor Analysis (FA)

$$x = \mu + \Lambda z + \epsilon$$

$$\begin{pmatrix} z \\ x \end{pmatrix} \sim N\left(\begin{pmatrix} 0 \\ \mu \end{pmatrix}, \Sigma\right) \quad \text{since } \mathbb{E}[z] = 0 \\ \mathbb{E}[x] = \mu$$

$$\hat{\Sigma}_{11} = \mathbb{E}[zz^T] = I \quad (z \sim N(0, I))$$

$$\begin{aligned} \hat{\Sigma}_{12} &= \mathbb{E}[z(x-\mu)^T] = \mathbb{E}[z z^T \Lambda^T] + \mathbb{E}[z \epsilon^T] \\ &= \Lambda^T \end{aligned}$$

$$\hat{\Sigma}_{21} = \hat{\Sigma}_{12} \quad (\Sigma \text{ is symmetric})$$

$$\begin{aligned} \hat{\Sigma}_{22} &= \mathbb{E}[(x-\mu)(x-\mu)^T] \\ &= \mathbb{E}[(\Lambda z + \epsilon)(\Lambda z + \epsilon)^T] \\ &= \mathbb{E}[\Lambda z z^T \Lambda^T] + \mathbb{E}[\epsilon \epsilon^T] \\ &= \Lambda \Lambda^T + \Phi \end{aligned}$$

$$\Sigma = \begin{bmatrix} I & \Lambda^T & \nearrow \text{Diagonal matrix.} \end{bmatrix}$$

$$[ \wedge \quad \Lambda \Lambda^T + \frac{1}{\lambda} I ]$$

EM Algorithm?

E-STEP:  $Q_i(z) = P(z^{(i)} | x^{(i)}, \theta)$  - use conditional

M-STEP: we know how to estimate.

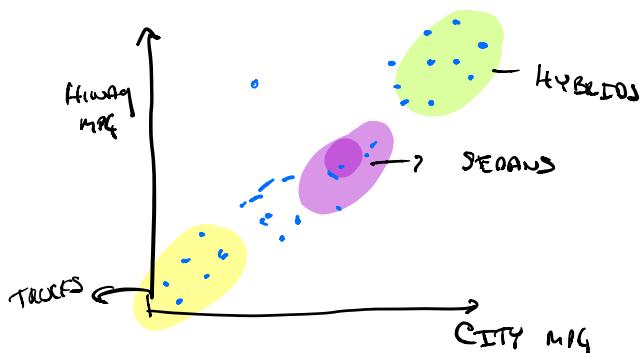
Summary:

- WE SAW THAT FOR CONSTRAINED GMM
- WE LEARNED **FACTOR ANALYSIS (FA)**
- WE SAW THAT ESTIMATES PARAMETERS OF FA WITH EM

PCA: Principal Component Analysis

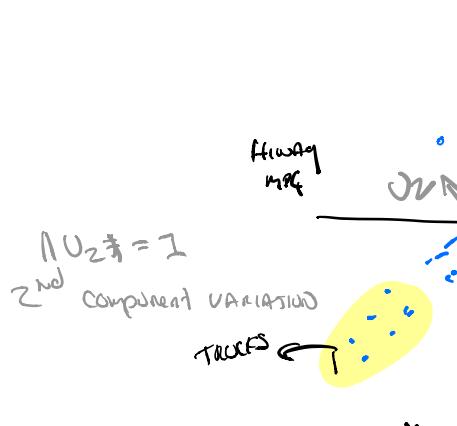
STRUCTURE	Prob.	Non-Prob.
"Cluster"	GMM Factor	K-MEANS
"SOSPARE"	FACTOR ANALYSIS	PCA

Ex: Given pairs about cars (Hwymp, Citymp)



Question: "Good Mag"

$$x^{(1)} \dots x^{(n)} \in \mathbb{R}^d$$



Component d Principal  
VARIATION

CENTER DATA

$$\mu = \frac{1}{n} \sum_i x^{(i)}$$

$$x^{(i)} \mapsto x^{(i)} - \mu$$

$$\|U_2\| = 1$$

$\geq 2^{\text{nd}}$  component variation

$$\|U_1\| = 1$$

CITY MAG

$$U_1 \cdot U_2 = 0$$

$$U_i \cdot U_j = \delta_{ij} \quad (\text{orthonormal basis})$$

$U_1$  is "How good is mag"

$U_2$  is "Difference between highway and city"

$$x = \alpha_1 U_1 + \alpha_2 U_2$$

→ Keeping this one term

$x^{(i)}$  keep around  $\alpha_1^{(i)}$  as one number instead of 2.

What we're thinking about is when we have 1000s of dimensions

and we want to find a few important ones

$$\mathbb{R}^{1000} \rightarrow \mathbb{R}^m \text{ or } \mathbb{R}^2 \text{ for visualization.}$$

$$U_i \text{ s.t. } \|U_i\| = 1 \text{ and } U_i \cdot U_j = \delta_{ij} \quad i = 1 \dots n \quad U_i \in \mathbb{R}^n$$

$$x = \sum \alpha_i U_i \quad (\text{write in a basis})$$