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In this chapter, we will look at autoencoders. This chapter is a theoretical one, covering the mathematics and the fundamental concepts of autoencoders. We will discuss what they are, what the limitations are, the typical use cases, and we will look at some examples. We will start with a general introduction to autoencoders, and we will discuss the role of the activation function in the output layer and the loss function. We will then discuss what the reconstruction error is. Finally, we will look at typical applications as dimensionality reduction, classification, denoising, and anomaly detection.

# What is an autoencoder

As we have seen in many previous chapters, neural networks are typically used in a supervised setting. Meaning that for each training observation we will have one label or expected value . During training, the neural network model will learn the relationship between the input data and the expected labels. Now suppose we have only unlabeled observations, meaning we only have our training dataset , made of the observations with

Where in general with . Autoencoders were first introduced[[1]](#footnote-1) by Rumelhart, Hinton, and Williams in 1986 for such a case (called unsupervised learning) with the goal of learning to reconstruct the input observations with the lowest error possible*[[2]](#footnote-2)*.

Why would one want to learn to reconstruct the input observations? If you have problems imagining what that means, think of having a dataset made of images. An autoencoder would be an algorithm that can give as output an image that is as similar as possible to the input one. You may be confused, as there is no apparent reason of doing so. To better understand why autoencoders are useful we need a more informative (although not yet unambiguous) definition.

Definition: an autoencoder is a type of algorithm with the primary purpose of learning an "informative" representation of the data that can be used for different applications*[[3]](#footnote-3)* by learning to reconstruct a set of input observations well enough.

To better understand autoencoders we need to refer to their typical architecture, visualized in Figure 25.1. The autoencoders' main components are three: an encoder, a latent feature representation, and a decoder. The encoder and decoder are simply functions, while with the name *latent feature representation,* one typically intends a tensor of real numbers (more on that later). Generally speaking, we want the autoencoder to reconstruct the input well enough. Still, at the same time, it should create a latent representation (the output of the **encoder** part in Figure 25.1) that is useful and meaningful. For example, latent features on hand-written digits[[4]](#footnote-4) could be the number of lines required to write each number or the angle of each line and how they connect. Learning how to write numbers certainly does not require to learn the gray values of each pixel in the input image. We humans do not certainly learn to write by filling pixels with gray values. While learning, we extract the essential information that will allow us to solve a problem (writing digits, for example). This latent representation (*how* to write each number) can then be very useful for various tasks (for instance, classification or clustering) or simply understanding the essential features of a dataset.

Chart, diagram

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Figure 25.1: general structure of an autoencoder.

In most typical architectures, the encoder and the decoder are neural networks[[5]](#footnote-5) (that is the case we will discuss at length in this chapter) since they can be easily trained with existing software libraries such as TensorFlow or PyTorch with backpropagation.

In general, the encoder can be written as a function

Where (the latent feature representation) is the output of the **encoder** block in Figure (25.1) when we evaluate it on the input . The **decoder** (and the output of the network that we will indicate with ) can be written then as a second generic function of the latent features

Training an autoencoder simply means finding the and that satisfy

Where indicates a measure of how the input and the output of the autoencoder differ (more on that later) and the expected value (or, in other terms, the mean over all observations). Depending on how one designs the autoencoder, it may be possible to find and so that the autoencoder learns to reconstruct the output perfectly, thus learning the identity function. This is not very useful, as we discussed at the beginning of the chapter, and to avoid this possibility, regularization in some form is required.

**Note** We want the autoencoder to reconstruct the input well enough. Still, at the same time, it should create a latent representation (the output of the encoder) that is useful and meaningful.

Regularization can be enforced in two main ways:

* Adding a "bottleneck," or in other words making the latent feature's dimensionality lower (often much lower) than the input's.
* Enforce sparsity in the latent feature output.

In this chapter we will look at the first method in detail, but to understand the second, it simply means using a regularization term, for example regularization. In other words, finding the best and that satisfy

Where are the outputs of the layer[[6]](#footnote-6). Both methods are effective (and sometimes applied at the same time). However for practical reasons, we will concentrate in this chapter only on the first method as it is the most often used in practical applications and often easier to implement in code.

We turn now to a specific type of autoencoders: those that build and with feed-forward networks.

# Feed Forward Autoencoders

A Feed-Forward Autoencoder (FFA) is a neural network made of dense layers[[7]](#footnote-7) with a specific architecture, as can be schematically seen in Figure (25.2).



Figure 25.2: A typical architecture of a Feed-Forward Autoencoder. The number of neurons in the layers at first goes down as we move through the network until it reaches the middle and then starts to grow again until the last layer has the same number of neurons as the input dimensions.

A typical FFA architecture (although it is no mandatory requirement) has an odd number of layers and is symmetrical with respect to the middle layer. Typically, the first layer has a number of neurons (the size of the input observation ). As we move toward the center of the network, the number of neurons in each layer drops in some measure. The middle layer (remember we have an odd number of layers) usually has the smallest number of neurons. The fact that the number of neurons in this layer is smaller than the size of the input is the bottleneck we mentioned earlier, thus adding regularization to this kind of autoencoders.

In almost all practical applications, the layers after the middle one are a mirrored version of the layers before the middle one. For example, an autoencoder with 3 layers could have the following numbers of neurons: , and then (supposing we are working on a problem where the input dimension is ). All the layers up to and including the middle one, make what is called the **encoder**, and all the layers from and including the middle one (up to the output) make what is called the **decoder**, as you can see depicted in Figure (25.2). If the FFA training is successful, the result will be a good approximation of the input, in other words . What is essential to notice is that the decoder can reconstruct the input by using only a much smaller number () of features than the input observations initially have (). The output of the middle layer are also called a *learned representation* of the input observation .

**Note** The **encoder** can reduce the number of dimensions of the input observation () and create a learned representation (of the input that has a smaller dimension . This learned representation is enough for the **decoder** to reconstruct the input accurately (if the autoencoder training was successful as intended).

## Activation Function of the Output Layer

In autoencoders based on neural networks, the output layer's activation function plays a particularly important role. The most used functions are ReLU and sigmoid. Let us look at both and look at some tips on when to use which and why you should choose one instead of the other.

### ReLU

The activation function can assume all values in the range . As a remainder, its formula is

This choice is good when the input observations assume a wide range of positive values.

If the input can assume negative values, the ReLU is, of course, a terrible choice, and the identity function is a much better choice.

**Note** ReLU activation function for the output layer is well suited for cases when the input observations assume a wide range of positive real values.

### Sigmoid

The sigmoid function can assume all values in the range . As a remained its formula is

This activation function can only be used if the input observations are all in the range or if you have normalized them to be in that range. Consider as an example the MNIST dataset. Each value of the input observation (one image) is the gray values of the pixels that can assume any value from to. Normalizing the data by dividing the pixel values by would make each observation (each image) have only pixel values between and . In this case, the sigmoid would be a good choice for the output layer's activation function.

**Note** The sigmoid activation function for the output layer is a good choice in all cases where the input observations assume only values between and or if you have normalized them to assume values in the range .

## Loss Function

As with any neural network model, we need a loss function to minimize. This loss functions should measure how big is the difference between the input and output . If you remember the explanations at the beginning, you will realize that our loss function will be

Where for FFAs, and will be the functions that are obtained with dense layers, as discussed in the previous sections. Remember that an autoencoder is trying to learn an approximation of the identity function; therefore, you want to find the weights in the network that gives you the smallest difference according to some metric () between and . Two loss functions are widely used for autoencoders: Mean Squared Error (MSE) and Binary Cross-Entropy (BCE). Let us have a more in-depth look at both since they can only be used when specific requirements are met.

### Mean Square Error

Since an autoencoder is trying to solve a regression problem, the most common choice as a loss function is the Mean Square Error (MSE):

The symbol indicates the norm of a vector[[8]](#footnote-8), and is the number of the observation in the training dataset. This loss function is particularly well suited when the inputs are real and can assume any value. It can be used in almost all cases, independently of how you choose your output layer activation function or how you normalize the input data.

It is easy to show that the minimum of is found for . To prove it, let us calculate the derivative of with respect to a specific observation Remember that the minimum is found when the condition

is met for all . To simplify the calculations, let us assume that the inputs are one dimensional[[9]](#footnote-9) and let us indicate them with . We can write

Equation (25.1) is satisfied when as can be easily seen from Equation (25.1), as we wanted to prove. To be precise, we also need to show that

This is easily proved as we have

that is greater than zero, therefore confirming our assumption that for we indeed have a minimum.

### Binary Cross-Entropy

If the activation function of the output layer of the FFA is a sigmoid function, thus limiting neuron outputs to be between 0 and 1, and the input features are normalized to be between 0 and 1 we can use as loss function the binary cross-entropy, indicated here with . Note that this loss function is typically used in classification problems, but it works beautifully for autoencoders. The formula for it is

Where the sum is over the entire set of observations. Can we prove that minimizing this loss function is equivalent to reconstructing the input as well as possible? Let us calculate where has a minimum with respect to . In other words, we need to find out what values should assume to minimize . As we have done for the MSE, to make the calculations easier, let us consider the simplified case where and are one-dimensional and let us indicate them with and .

To find the minimum of a function, as you should know from calculus, we need the first derivative of . In particular we need to solve the set of equations

In this case it is easy to show that the binary cross-entropy is minimized when for .

To find when the is minimized we can derive with respect to a specific input

Now remember that we need to satisfy the condition

That can happen only if as can be seen from Equation (25.2). To make sure that this is a minimum we need to evaluate the second derivative. Since the point for which the first derivative is zero is a minimum only if

We can calculate the second derivative at the minimum point easily

Now remember that . We can immediately see that the denominator of the previous formula is greater than zero. The nominator is also clearly greater than zero since . Dividing two positive numbers gives a positive number, thus we have just proved that

The minimum of the cost function is reached when the output is exactly equal to the inputs, as we wanted to prove.

**Note** an essential prerequisite for using the binary cross-entropy loss function is that the inputs **must** be normalized between 0 and 1 and that the activation function for the last layer must be a *sigmoid* or *softmax* function.

## Reconstruction Error

The reconstruction error (RE) is a metric that gives you an indication of how good (or bad) the autoencoder was able to reconstruct the input observation . The most typical RE used is the MSE

That can be easily calculated. The RE is used often when doing anomaly detection with autoencoders, as we will explain later. There is an easy intuitive explanation of the reconstruction error. When the RE is significant, the autoencoder could not reconstruct the input well, while when it is small, the reconstruction was successful. Figure (25.3) shows an example of big and small reconstruction errors when an autoencoder tries to reconstruct an image.

Diagram

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Figure 25.3: An example of big and small reconstruction error when an autoencoder tries to reconstruct an image.

## Example: reconstruction of hand-written digits

Let us now see how an autoencoder performs with a real example, using the MNIST dataset. This dataset[[10]](#footnote-10) contains 70000 hand-written digits from 0 to 9. Each image is pixels with only gray values, that means that we have 784 features (the pixel gray values) as inputs. Let us start with an autoencoder with 3 layers with the numbers of neurons in each layer equal to . Note that the first and last layers **must** have a dimension equal to the input dimensions. For this example, we used the Adam optimizer[[11]](#footnote-11), as loss function the cross-entropy and we trained the model for epochs with a batch size of . In Figure (25.4) you can see two lines of images of digits. The line at the top contains ten random images from the original dataset, while the ones at the bottom are the reconstructed images with the autoencoder we just described.

A picture containing sign

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Figure 25.4: In the top line, you can see the original digits from the MNIST dataset. In contrast, the line below contains the digits reconstructed by the autoencoder with number of neurons equal to (784, 16, 784).

It is impressive that to reconstruct an image with 784 pixels, 10 classes and 70000 images only 16 features are needed to have a result that, although not perfect, allows us to understand almost entirely what digit was used as input. Increasing the middle layer's size to (and leaving all other parameters the same) gets a much better result as you can see in Figure (25.5).

A picture containing text

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Figure 25.5: In the top line you can see the original digits from the MNIST dataset. While the line below are the digits reconstructed by the autoencoder with number of neuraons equal to (784, 64, 784).

This tells us that the relevant information on how to write digits is contained in a much lower number of features than 784.

**Note** An autoencoder with a middle layer smaller than the input dimensions (a bottleneck) can be used to extract the essential features of an input dataset creating a learned representation of the inputs given by the function . Effectively an FFA can be used to perform dimensionality reduction.

The FFA will not recreate the input digits well if the number of neurons in the middle layer is reduced too much (if the bottleneck is too extreme). Figure (25.6) shows the reconstruction of the same digits with an autoencoder with only 8 neurons in the middle layer. With only 8 neurons in the middle layer, you can see that some reconstructed digits are wrong. As you can see in Figure (25.6) the 4 is reconstructed as a 9 and a 2 is reconstructed to something that resembles a 3.

A close up of a sign

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Figure 25.6: In the top line you can see the original digits from the MNIST dataset. In contrast, the line below contains the digits reconstructed by the autoencoder with number of neurons equal to (784, 8, 784).

In Figure (25.7), you can compare the reconstructed digits by all the FFAs we have discussed.



Figure 25.7: In the top line, you can see the original digits from the MNIST dataset. The second line of digits contains the digits reconsructed by the FFA (784,8,784), the third by the FFA (784,16,784), and the last one by the FFA (784,64,784).

From Figure (25.7) you can see how, increasing the middle layer's size, the reconstruction gets better and better, as we expected.

For these examples, we have used the binary cross entropy as loss function, but the MSE would have worked also well, and results can be seen in Figure (25.8).

Calendar

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Figure 25.8: In the top line, you can see ten random original digits from the MNIST dataset. The second line of digits contains the digits reconstructed with an FFA with 16 neurons in the middle layer and the binary cross-entropy as the loss function. The last line contains images reconstructed with the MSE as loss function.

# Autoencoders Applications

## Dimensionality Reduction

As we mentioned in this chapter, using the bottleneck regularization method, the latent features will have a dimension that is smaller than the dimensions of the input observations . The *encoder* part (once trained) does naturally (by design) dimension reduction producing real numbers. One can use the latent features for various tasks, such as classification (as we will see in the next section) or clustering. I would like to point out some of the advantages of dimensionality reduction with an autoencoder compared to a more classical PCA approach. The autoencoder has one main benefit from a computational point of view: it can deal with a very big amount of data efficiently since its training can be done with mini-batches, while PCA, one of the most used dimensionality reduction algorithms, needs to do its calculations using the entire dataset. PCA is an algorithm that projects a dataset on the eigenvectors of its covariance matrix[[12]](#footnote-12). The default method uses space for data in . This is, in many cases, not computationally feasible, and the algorithm does not scale up with increasing dataset size. This may seem irrelevant, but in many practical applications, the amount of data and the number of features is so big that PCA is not a practical solution from a computational point of view.

**Note** The use of an autoencoder for dimensionality reduction has one main advantage from a computational point of view: it can deal with a very big amount of data efficiently since its training can be done with mini-batches.

## Classification

### Classification with Latent Features

Let us now suppose that we want to classify our input images of the MNIST dataset. We can simply use all the features, in our case, the pixel values of the images. We can simply use an algorithm as kNN for illustrative purposes. Doing it with nearest neighbors on the training MNIST dataset (with 60000 images) will take around 16.6 minutes[[13]](#footnote-13) (ca.1000 sec) and gets you an accuracy on the test dataset of 10000 images of . However, what happens if we use this algorithm not with the original dataset, but with the latent features ? For example, if we consider an FFA with neurons in the middle layer and again train a kNN algorithm on the latent features we get an accuracy of 89% in 1.1 sec. We get a gain of a factor of 1000 in running time, for a loss of 7.4% in accuracy[[14]](#footnote-15).

|  |  |  |
| --- | --- | --- |
| Input Data | Accuracy | Running Time |
| Original data | 96.4% | sec. min. |
| Latent Features g | 89% | 1.1 sec. |

Table 25.1: the different in accuracy and running time when applying the kNN algorithm to the original 784 features or the 8 latent features for the MNIST dataset.

Using features allow us to get a very high accuracy in just one second.

We can do the same analysis with another dataset, the Fashion MNIST[[15]](#footnote-16) dataset (a dataset from Zalando very similar to the MNIST one, only with clothing images instead of hand-written digits) for illustrative purposes. The dataset has, as the MNIST one, 60000 training images and 10000 test ones. In Table 25.2 you can see the summary of the results of applying kNN to the testing portion of this dataset.

|  |  |  |
| --- | --- | --- |
| Input Data | Accuracy | Running Time |
| Original data | 85.4% | sec. min. |
| Latent Features | 79.9% | 1.2 sec. |
| Latent Features | 83.6% | 3.0 sec. |

Table 25.2: the difference in accuracy and running time when applying the kNN algorithm to the original 784 features with a FFA with 8 neurons and with a FFA with 16 neurons for the Fashion MNIST dataset.

It is exciting to note that with an FFA with 16 neurons in the middle layer, we reach an accuracy of 83.6% in just 3 sec. When applying a kNN algorithm to the original features (784), we get an accuracy only 1.8% higher but with a running time ca. 330 times longer.

**Note** Using autoencoders and doing classification with the latent features is a very viable technique to reduce the training time by several order of magnitude while incurring a minor drop in accuracy.

### Curse of dimensionality – a small detour

Is there any other reason why we want to do dimensionality reduction before doing any classification? Reducing running time is one reason, but another important one plays a significant role when the input dimension is very large, i.e., the datasets that have a very high number of features: the curse of dimensionality. To understand why we need to make a quick detour in the problem of high dimensionality classification and discuss the *curse of dimensionality*. Let us consider the unit cube with an integer and points in it distributed randomly. How big should be the length of the smallest hyper-cube to contain at least point? We can easily calculate it as

We can easily calculate this value of for various values of . Let us suppose that we consider and summarize the results in Table 25.3.

|  |  |
| --- | --- |
| d | l |
| 2 | 0.003 |
| 10 | 0.50 |
| 100 | 0.93 |
| 1000 | 0.99 |

Table 25.3: Length of the smallest hyper-cube to contain at least point from a population of randomly distributed points.

Furthermore, as you can see the data becomes so sparse in high dimensions that you need to consider the entire hyper cube to capture one single observation. When the data becomes so sparse the number of observations you will need to train an algorithm properly becomes much bigger than the size of existing datasets.

We could look at this differently. Let us consider now a small hypercube of side . How many observations we will find on average in this small portion of the hypercube? This is easy to calculate and is given by

You can see that this number is very small for high values of . For example, if we consider is easy to see that we would need more observations than atoms in the universe[[16]](#footnote-17) to find at least one observation in that small portion of the hypercube.

**Note** Doing dimensionality reduction is a very viable method for reducing dramatically running time while incurring in an only small drop in accuracy. In high dimensionality datasets this becomes fundamental due to the curse of dimensionality.

## Anomaly Detection

Autoencoders are often used to perform anomaly detection on the most different datasets. The best way to understand how anomaly detection works with autoencoders is to look at it with a practical example. Let us consider an autoencoder with only three layers with 784 neurons in the first, 64 in the latent feature generation layer, and again 784 neurons in the output layers. We will train it with the MNIST dataset and in particular with the 60000 training portion of it as we have done in the previous sections of the chapter. Now let us consider the Fashion MNIST dataset. Let us choose an image of a shoe (see Figure 25.9) from this dataset

A picture containing drawing

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Figure 25.9: one random image from the Zalando MNIST dataset.

and add it to the testing portion of the MNIST dataset. The original testing portion of MNIST has 10000 images. With the shoe we will have a 10001 images dataset. How can we use an autoencoder to find the shoe automatically in those 10001 images? Note that the shoe is an "outlier", an "anomaly" since it is an entirely different image class than hand-written digits. To do that we will take the autoencoder we trained with the 60000 MNIST images and with it we will calculate the reconstruction error for the 10001 test images.

The main idea is that since the autoencoder has only seen hand-written digits images, it will not be able to reconstruct the shoe image. Therefore we expect this image to have the biggest reconstruction error. We can check if that is the case by taking the top 2 reconstruction errors. For this example, we have used the MSE for the reconstruction error. You can check the code of this example at <https://adl.toelt.ai>. The shoe has the highest reconstruction error: 0.062. The autoencoder is not able to reconstruct the image as it can be seen from Figure 25.10.

Graphical user interface

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Figure 25.10: the shoe and the autoencoder's reconstruction trained on the 60000 hand-written images of the MNIST dataset. This image has the biggest RE in the entire 10001 test dataset we built with a value of 0.062.

The second biggest RE is slightly less than one third of that of the shoe: 0.022, indicating that the autoencoder is doing quite a good job in understanding how to reconstruct hand-written digits. You can see the image with the second biggest RE in Figure 25.11. This image could also be classified as an outlier, as is not completely clear if it is a 4 or an incomplete 9.

A picture containing drawing

Description automatically generatedFigure 25.11: the image with the second biggest RE in the 10001 test dataset: 0.022.

The readers with most experience may have noticed that we trained our autoencoders on a dataset without any outliers and applied it to a second dataset with outliers. This is not always possible as very often the outliers are not known and are lost in a big dataset. In general, one wants to find outliers in a single big dataset without any information on how many there are or how they look like. Generally speaking, anomaly detection can be done following the main steps below.

1. One train an autoencoder on the entire dataset (or if possible, on a portion of the dataset known **not** to have any outlier).
2. For each observation (or input) of the portion of the dataset known to have the wanted outliers one calculates the RE.
3. One sorts the observations by the RE.
4. One classifies the observations with the highest RE as outliers. Note that how many observations are outliers will depend on the problem at hand and require an analysis of the results and usually lot of knowledge of the data and the problem.

Note that if one train the autoencoder on the entire dataset at disposal, there is an essential assumption: the outliers are a negligible part of the dataset and their presence will not influence (or will influence in an insignificant way) how the autoencoder learns to reconstruct the observations. This is one of the reasons why regularization is so essential. If the autoencoders would learn the identity function, anomaly detection could not be done.

A classic example of anomaly detection is finding fraudulent credit card transactions (the outliers). This case usually presents ca. 0.1% fraudulent transactions and therefore this would be a case that would allow us to train the autoencoder on the entire dataset.

**Note** If one train the autoencoder on the entire dataset at disposal, there is an essential assumption: the outliers are a negligible part of the dataset and their presence will not influence (or will influence in an insignificant way) how the autoencoder learns to reconstruct the observations.

### Model Stability – a short note

Note that doing anomaly detection as described in the previous section seems easy, but those methods are prone to overfitting and give often inconsistent results. This means that training an autoencoder with a different architecture may well give different REs and therefore other outliers. There are several ways of solving this problem, but one of the simplest ways of dealing with instability of results is to train different models and then take the average of the REs. Another often used technique involves taking the maximum of the REs evaluated from several models.

**Note** Anomaly detection done with autoencoders is prone to problems as overfitting and unstable results. It is essential to be aware of these problems and check the results coming from different models to interpret the results correctly.

Note that this section serves to give you some pointers and is not meant to be an exhaustive overview on how to solve this problem.

Like autoencoders ensembles[[17]](#footnote-18), more advanced techniques are also used to deal with problems of instable results coming, for example, from small datasets.

## Denoising autoencoders

Denoising autoencoders[[18]](#footnote-19) are developed to auto-correct errors (noise) in the input observations. As an example, imagine the hand-written digits we considered before where we added some noise (for example Gaussian noise) in the form of changing randomly the gray values of the pixels. In this case the autoencoders should learn to reconstruct the image without the added noise. As a concrete example, consider the MNIST dataset. We can add to each pixel a random value generated by a normal distribution scaled by a factor (you can check the code at <https://adl.toelt.ai> in chapter 25). We can train an autoencoder using as input the noisy images, and as output the original images. The model should learn to remove the noise, since it is random in nature and have no relationship with the images.

In Figure (25.12) you can see the results. In the left column you see the noisy images, in the middle the original ones and on the right the de-noised images. It is quite impressive how well it works. Figure 25.12 has been generated by training a FFA autoencoder with 3 layers and 32 neurons in the middle layer.

A picture containing qr code

Description automatically generated

Figure 25.12: results of a denoising FFA autoencoder with 3 layers and 32 neurons in the middle layer. The noise has been generating adding a real number between 0 and 1 taken from a normal distribution. For details see the code at <https://adl.toelt.ai> in chapter 25.

# Beyond FFA – autoencoders with convolutional layers

In this chapter we have described autoencoders with a feed-forward architecture. There is no rule and autoencoders with convolutional layers works as well, and often (especially when dealing with images) are much more efficient. For example, in Figure (25.13) you can see a comparison of the results of a FAA (with architecture (784,32,784)) and of a Convolutional Autoencoder (CA) (with architecture ((28x28), (26x26x64), (24x24,32), (26x26x64), (28x28); keep in mind the layers are convolutions, so the first two numbers indicate the tensor dimensions and the third the number of kernels, that in this example had a size of 3x3). The two autoencoders have been trained with the same parameters (epochs, mini-batch size, etc.). You can see how a CA gives better results than a FAA, since we are dealing with images. To be fair, note that the feature generating layer is only marginally smaller than the input layer in this example. The purpose of this example is only to show you how also convolutional autoencoders are a viable solution that works very well in many practical applications.

A picture containing qr code

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Figure 25.13: comparison of the results of a FAA (with architecture (784,32,784)) and of a Convolutional Autoencoder (CA) (with architecture ((28x28), (26x26x64), (24x24,32), (26x26x64), (28x28); keep in mind the layers are convolutions, so the first two numbers indicate the tensor dimensions and the third the number of kernels, with kernel size 3x3). The two autoencoders have been trained with the same parameters. You can check the code at <https://adl.toelt.ai> in chapter 25.

Another important aspect is that the feature generating layer could be a convolutional layer but could also be a dense one. There is not fix rule and testing is required to find the best architecture for your problem and how you want to model your latent features: as a tensor (multi-dimensional array) or as a one-dimensional array of real numbers.

# Exercises

Exercise 1

List the most useful tasks you can use an autoencoder for. Can you think of an application in your field of work?

Exercise 2

Can you explain briefly what is a sparse autoencoder? How is similar to an autoencoder with a bottleneck?

Exercise 3

How do you measure (with which metric) the performance of an autoencoder? List the most commonly used metrics that you can use. Can you think of any additional metric, in addition to those discussed in this chapter, that could be used?

Exercise 4

Describe how anomaly detection work with autoencoders.

# Further Readings

Deep Learning Tutorial from Stanford University

<http://ufldl.stanford.edu/tutorial/unsupervised/Autoencoders/>

Building autoencoders in Keras

<https://blog.keras.io/building-autoencoders-in-keras.html>

Introduction to autoencoders in TensorFlow

<https://www.tensorflow.org/tutorials/generative/autoencoder>

Bank, D., Koenigstein, N., and Giryes, R., “Autoencoders”, arXiv e-prints, 2020,

<https://arxiv.org/abs/2003.05991>

R. Grosse, University of Toronto, Lecture on autoencoders

<http://www.cs.toronto.edu/~rgrosse/courses/csc321_2017/slides/lec20.pdf>

1. You can check Rumelhart, D.E., Hinton, G.E. Williams, R.J.: Parallel distributed processing: Explorations in the microstructure of cognition, Vol. 1. Chap. Learning Internal Representations by Error Propagation, pp. 318-162, MIT Press, Cambridge, MA, USA (1986). [↑](#footnote-ref-1)
2. In this chapter we will discuss at length what we mean with error here. [↑](#footnote-ref-2)
3. Bank, D., Koenigstein, N., and Giryes, R., Autoencoders, <https://arxiv.org/abs/2003.05991> [↑](#footnote-ref-3)
4. Imagine the MNIST dataset that you have seen many times in this book so far. [↑](#footnote-ref-4)
5. For example, if the encoder and the decoder are linear functions, you get what is called a linear autoencoder. See for more information Baldi, P., Hornik, K.: Neural networks and principal component analysis: Learning from examples without local minima, Neural Netw. **2**(1), 53-58 (1989). [↑](#footnote-ref-5)
6. Bank, D., Koenigstein, N., and Giryes, R., Autoencoders, <https://arxiv.org/abs/2003.05991> [↑](#footnote-ref-6)
7. A dense layer is simply a set of neurons that gets their inputs from the previous layer. Each neuron in a dense layer gets as input the output of all neurons in the previous layer. [↑](#footnote-ref-7)
8. The norm of a vector is simply the square root of the sum of the square of the components. [↑](#footnote-ref-8)
9. If we did not make this assumption, one would have to calculate the gradient of the loss function instead of the simple derivative. [↑](#footnote-ref-9)
10. More information on the dataset can be found here: <http://yann.lecun.com/exdb/mnist/>. [↑](#footnote-ref-10)
11. You can find the entire code at the address <https://adl.toelt.ai>. [↑](#footnote-ref-11)
12. Akshay Balsubramani, Sanjoy Dasgupta, and Yoav Freund. The fast convergence of incremental pca. In Advances in neural information processing systems, pages 3174–3182, 2013. [↑](#footnote-ref-12)
13. The examples have been run on Google Colab. [↑](#footnote-ref-13)
14. You can run those tests yourself going to Chapter 25 at <https://adl.toelt.ai>. [↑](#footnote-ref-15)
15. <https://research.zalando.com/welcome/mission/research-projects/fashion-mnist/> [↑](#footnote-ref-16)
16. <https://www.universetoday.com/36302/atoms-in-the-universe/> [↑](#footnote-ref-17)
17. See for example <https://saketsathe.net/downloads/autoencode.pdf>. [↑](#footnote-ref-18)
18. Vincent, P., Larochelle, H. Bengio, Y. Manzagol, P.A.: Extracting and composing robust features with denoising autoencoders. In: Proceedings of the 25th International Conference on Machine Learning, ICML ’08, pp. 1096-1103. ACM, New York, NY USA (2008) [↑](#footnote-ref-19)