Decision trees tend to overfit to very different trees. Solution: Introduce randomised algorithms. 1. Bagging = Bootstrap aggregation  $S = \frac{1}{2} \frac{1}{2}$ (1) Bootstapping: Produce B samples from Sall of size N by random sampling of size N by random sampling with repracement: Shots, (2) Models. From each of the B samples obtain DT: ADT B

STATE

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B

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STATE In each Sb free will be repeated samples and absent samples from the onfinal S

Random forests add an additional devel of randomisation bootstap sample Severate a 156 In DT je [1, -, P] maximise overall predictors Rj E Zily random, subret of subret of severiptor At each Split choose random subset of descriptors in the p descriptors IRF = P P Chosen at random anon fre [1, ..., P] C RF [PI, Pz, Ps 1- ] 5 Repeat 5 times S=1,...,S

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The result is an ensemble of trees: S JEFF 15 = random forest K is defined on each of the spolits. The predictor is the aggregation of  $\{\hat{f}_{[\vec{p}_{k}]}\}_{s=1}^{r_{k}}$ · Regression: average of of FRF ] 5=1 · Clessifration: ) Tipp [5]

Some comments:

(1) loss of interpretability:

with aggregation we lose

The direct connection

with The descriptors.

\* Parameters (hyper-parameters): ·S = # of tres. Not very suntitive € Classification +> 1 Regression +>5 · Minimumberf size: # of descriptors allowed at each  $\tilde{p} \sim \frac{P}{3}$  descriptor. [If \$=1, trees are very unconcluted].

II \$p=p; trees are correlated

\* Britshap bys as were extra knowledge: For every sample Sb, there are some out-of-bag' samples: out-of-bay ever = 00B ever ear be used for · Example of ensemble methods RF is an example of an ensemble method. (1) Mixing different classifiers (2) Generating ensemble of trees by boosting

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Classification or geometric suparation.

Assume 
$$X^{(i)} = (X_1^{(i)}, ..., X_p^{(i)})$$
  $Y^{(i)} \in \{-1, +1\}$ 

Assume  $X^{(i)} \in \mathbb{R}^2$   $X^{(i)} = (X_1^{(i)}, X_2^{(i)})$ 
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In R2: look for:

$$X_2 = W X_1 + b$$

$$\vec{x} \cdot \vec{w} + b = 0$$
 $\vec{w} = (w, -1)$ 
 $(w, -1) \cdot (x_1, x_2) + b = 0$ 

$$\vec{x} \cdot \vec{\beta} = \vec{x} \cdot \vec{w} + \vec{b} = 0$$

$$\vec{x} = \begin{pmatrix} \vec{x}_1 \\ \vec{x}_2 \\ \vec{y}_1 \end{pmatrix} \vec{\beta} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_1 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_2 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_3 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}_2 \\ \vec{w}_3 \end{pmatrix} \vec{\psi} = \begin{pmatrix} \vec{w}_1 \\ \vec{w}$$

Equation of a hyperplane

Find the hyperplane  $\vec{x} \cdot \vec{w} + \vec{b} = 0$  $(\vec{w}, \vec{b})$  to be found.

$$C_{1,C_{2}} \in \mathbb{R}^{+}$$
  $\begin{cases} \vec{x}^{(i)} \cdot \vec{w} + b > C_{1} & \text{if } y^{(i)} = +1 \\ \vec{x}^{(i)} \cdot \vec{w} + b < -C_{2} & \text{if } y^{(i)} = -1 \end{cases}$