Training Neural Networks: Optimization

Intro to Deep Learning, Spring 2018
Quick Recap

- Gradient descent, Backprop
Quick Recap: Gradient Descent

- Gradient descent to find the minimum of any “loss” function $f(w)$:
  - Initialize $w_0$
  - Iterate until the gradient (nearly) vanishes
    \[
    w_k = w_{k-1} - \eta \nabla_w f(w_{k-1})^T
    \]
Quick Recap: Training a network

• Define a total “loss” over all training instances
  – Quantifies the difference between desired output and the actual output, as a function of weights

• Find the weights that minimize the loss

\[
L(W) = \frac{1}{N_x} \sum_X \text{div}(f(X; W), D(X))
\]

\[
\hat{W} = \arg \min_W L(W)
\]
Quick Recap: Training networks by gradient descent

\[ L(W) = \frac{1}{N_x} \sum_x \text{div}(f(X; W), D(X)) \]

\[ \nabla_W L(W) = \frac{1}{N_x} \sum_x \nabla_W \text{div}(f(X; W), D(X)) \]

Solved through gradient descent as

\[ \hat{W} = \arg \min_W L(W) \quad \Rightarrow \quad W_k = W_{k-1} - \eta \nabla_W L(W)^T \]

• The gradient of the total loss is the average of the gradients of the loss for the individual instances

• The total gradient can be plugged into gradient descent update to learn the network
Quick Recap: Training networks by gradient descent

\[ L(W) = \sum_X \nabla_W L(W) = \sum_X \nabla_W \text{div}(f(X;W), D(X)) \]

\[ \hat{W} = \arg\min_W L(W) \]

\[ W_k = W_{k-1} - \eta \nabla_W L(W)^T \]

- The gradient of the total loss is the average of the gradients of the loss for the individual instances.
- The total gradient can be plugged into gradient descent update to learn the network.
Quick recap of backprop: forward pass

- **Forward pass**: Compute output and all intermediate variables in the network, for the input $X$
Quick recap of backprop: forward pass

- **Forward pass**: Compute output and all intermediate variables in the network, for the input $X$
Quick recap of backprop: forward pass

• **Forward pass**: Compute output and all intermediate variables in the network, for the input $X$
Quick recap of backprop: forward pass

- **Forward pass**: Compute output and all intermediate variables in the network, for the input $X$
Quick recap of backprop: forward pass

- **Forward pass**: Compute output and all intermediate variables in the network, for the input $X$
Quick recap of backprop: forward pass

- **Forward pass**: Compute output and all intermediate variables in the network, for the input $X$
Quick recap of backprop: forward pass

- **Forward pass**: Compute output and all intermediate variables in the network, for the input $X$
The Forward Pass

• Set $y_0 = x$

• For layer $k = 1$ to $N$:
  — Recursion:
    \[ z_k = W_k y_{k-1} + b_k \]
    \[ y_k = f_k(z_k) \]

• Output:
  \[ Y = y_N \]
Quick Recap: Backprop. Forward pass

- **Forward pass**: Compute output and all intermediate variables in the network, for the input $X$
- **Compute the divergence w.r.t. desired output**
Quick Recap: Backpropagation

- Now work your way \textit{backward} through the net to compute the derivative w.r.t each intermediate variable and each weight/bias
First compute the gradient of the divergence w.r.t. $Y$. The actual gradient depends on the divergence function.
Backprop

\[ \nabla_{z_N} \text{Div} = \nabla_Y \text{Div} \, J_Y(z_N) \]

Chain rule (vector format; note order of multiplication)
The backward pass

\[ z_N = W_N y_{N-1} + b_N \]

\[ \nabla_{W_N} Div = y_{N-1} \nabla_{z_N} Div \]

\[ \nabla_{b_N} Div = \nabla_{z_N} Div \]
Chain rule (vector format; note order of multiplication)
The backward pass

The Jacobian will be a diagonal matrix for scalar activations.

\[ \nabla_{z_{N-1}} \text{Div} = \nabla_{y_{N-1}} \text{Div} \, J_{y_{N-1}}(z_{N-1}) \]

The Jacobian will be a diagonal matrix for scalar activations.

Chain rule (vector format; note order of multiplication)
The backward pass

\[ z_{N-1} = W_{N-1}y_{N-2} + b_{N-1} \]

\[ \nabla_{W_{N-1}} \text{Div} = y_{N-2} \nabla_{z_{N-1}} \text{Div} \]

\[ \nabla_{b_{N-1}} \text{Div} = \nabla_{z_{N-1}} \text{Div} \]
The backward pass

\[ D_{iV}(Y, d) \]

\[ \nabla_{y_{N-2}} Div = \nabla_{z_{N-1}} Div W_{N-1} \]
The backward pass

\[ \nabla_{z_{N-2}} Div = \nabla_{y_{N-2}} Div J_{y_{N-2}}(z_{N-2}) \]
The backward pass

\[ \nabla_{z_1} \text{Div} = \nabla_{y_1} \text{Div} \quad J_{y_1}(z_1) \]
The backward pass

In some problems we will also want to compute the derivative w.r.t. the input

\[ \nabla_{w_1} \text{Div} = x \nabla_{z_1} \text{Div} \]

\[ \nabla_{b_1} \text{Div} = \nabla_{z_1} \text{Div} \]
The Backward Pass

- Set $y_N = Y$, $y_0 = x$
- Initialize: Compute $\nabla_{y_N} Div = \nabla_Y Div$

- For layer $k = N$ downto 1:
  - Recursion:
    \[
    \nabla_{z_k} Div = \nabla_{y_k} Div J_{y_k} (z_k)
    \]
    \[
    \nabla_{y_{k-1}} Div = \nabla_{z_k} Div W_k
    \]
  - Gradient computation:
    \[
    \nabla_{w_k} Div = y_{k-1} \nabla_{z_k} Div
    \]
    \[
    \nabla_{b_k} Div = \nabla_{z_k} Div
    \]
Neural network training algorithm

• Initialize all weights and biases \((W_1, b_1, W_2, b_2, \ldots, W_N, b_N)\)

• Do:
  – \(Err = 0\)
  – For all \(k\), initialize \(\nabla_{W_k} Err = 0, \nabla_{b_k} Err = 0\)
  – For all \(t = 1:T\)
    • Forward pass: Compute
      – Output \(Y(X_t)\)
      – Divergence \(Div(Y_t, d_t)\)
      – \(Err += Div(Y_t, d_t)\)
    • Backward pass: For all \(k\) compute:
      – \(\nabla_{W_k} Div(Y_t, d_t), \nabla_{b_k} Div(Y_t, d_t)\)
      – \(\nabla_{W_k} Err += \nabla_{W_k} Div(Y_t, d_t), \nabla_{b_k} Err += \nabla_{b_k} Div(Y_t, d_t)\)
    – For all \(k\), update:
      \[W_k = W_k - \frac{\eta}{T} (\nabla_{W_k} Err)^T; \quad b_k = b_k - \frac{\eta}{T} (\nabla_{W_k} Err)^T\]
  • Until \(Err\) has converged
Quick Recap

• Gradient descent, Backprop

• The issues with backprop and gradient descent
  – 1. Minimizes a loss which relates to classification accuracy, but is not actually classification accuracy
    • The divergence is a continuous valued proxy to classification error
    • Minimizing the loss is expected to, but not guaranteed to minimize classification error
  – 2. Simply minimizing the loss is hard enough.
Quick recap: Problem with gradient descent

- A step size that assures fast convergence for a given eccentricity can result in divergence at a higher eccentricity.
- Or result in extremely slow convergence at lower eccentricity.

\[ W_k = W_{k-1} - \eta \nabla_w L(W)^T \]

- A step size that assures fast convergence for a given eccentricity can result in divergence at a higher eccentricity.
- Or result in extremely slow convergence at lower eccentricity.
Quick recap: Problem with gradient descent

- The loss is a function of many weights (and biases)
  - Has different eccentricities w.r.t different weights
- A fixed step size for all weights in the network can result in the convergence of one weight, while causing a divergence of another
Quick recap: Problem with gradient descent

- Ideally: Have component-specific step size
  - Too many independent parameters (maintain a step size for every weight/bias)
- Adaptive solution: Start with a common step size
  - *Shrink* step size in directions where the weight oscillates
  - *Expand* step size in directions where the weight moves consistently in one direction

\[
W_k = W_{k-1} - \eta \nabla_W L(W)^T
\]
Quick Recap

• Gradient descent, Backprop
• The issues with backprop and gradient descent
  • Rprop and Momentum
Quick recap: Rprop

• RPROP: Independently update step size of every weight
  – But step size is independent of actual gradient
    • Gradient only used to determine direction of update
• Initialize stepsize $\eta_w = 1$ for all weights
  ▪ If $\text{sign}\left(\frac{\partial L(W_{k-1})}{w_{k-1}}\right) \text{sign}\left(\frac{\partial L(W_k)}{w_k}\right) > 0$: $\eta_w = \alpha \eta_w$, where $\alpha > 1$
  ▪ Else: $\eta_w = \beta \eta_w$, where $\beta < 1$
    – $k$ represent iteration (rule applies individually to every weight $w$ in the network)
• If the current gradient has the same sign as the last one, we are continuing to move in the same direction over consecutive steps
  – Test to check this: their product is positive
  – Increase the step size by a factor $\alpha$
• Otherwise, we are reversing direction
  – Have overshot the minimum and may be diverging
  – Decrease the step size by a factor $\beta$
Quick recap: Rprop

Note: Does not actually use the derivative values. Only the signs

• RPROP: Independently update step size of every weight
  – But step size is independent of actual gradient
    • Gradient only used to determine direction of update

• Initialize stepsize $\eta_w = 1$ for all weights
  ▪ If $\text{sign}\left(\frac{\partial L(W_{k-1})}{w_{k-1}}\right) \times \text{sign}\left(\frac{\partial L(W_k)}{w_k}\right) > 0$: $\eta_w = \alpha \eta_w$, where $\alpha > 1$
  ▪ Else: $\eta_w = \beta \eta_w$, where $\beta < 1$
    – $k$ represent iteration (rule applies individually to every weight $w$ in the network)

• If the current gradient has the same sign as the last one, we are continuing to move in the same direction over consecutive steps
  – Test to check this: their product is positive
    – Increase the step size by a factor $\alpha$

• Otherwise, we are reversing direction
  – Have overshot the minimum and may be diverging
    – Decrease the step size by a factor $\beta$
Quick recap: Momentum methods

Momentum
\[ \Delta W^{(k)} = \beta \Delta W^{(k-1)} - \eta \nabla_w \text{Err}(W^{(k-1)}) \]

Note: now a vector update rule (not component wise like rprop)

- Momentum: Retain gradient value, but *smooth out* gradients by maintaining a running average
  - Cancels out steps in directions where the weight value oscillates
  - Adaptively increases step size in directions of consistent change

Nestorov
\[ W_{\text{extend}}^{(k)} = W^{(k-1)} + \beta \Delta W^{(k-1)} \]
\[ \Delta W^{(k)} = \beta \Delta W^{(k-1)} - \eta \nabla_w \text{Err}(W_{\text{extend}}^{(k)}) \]
\[ W^{(k)} = W^{(k-1)} + \Delta W^{(k)} \]
Recap

• Neural networks are universal approximators
• We must *train* them to approximate any function
• Networks are trained to minimize total “error” on a training set
  – We do so through empirical risk minimization
• We use variants of gradient descent to do so
  – Gradients are computed through backpropagation
Recap

• Vanilla gradient descent may be too slow or unstable

• Better convergence can be obtained through
  – Second order methods that normalize the variation across dimensions
  – Adaptive or decaying learning rates that can improve convergence
  – Methods like Rprop that decouple the dimensions can improve convergence
  – Momentum methods which emphasize directions of steady improvement and deemphasize unstable directions
Moving on: Topics for the day

• Incremental updates
• Revisiting “trend” algorithms
• Generalization
• Tricks of the trade
  – Divergences..
  – Activations
  – Normalizations
Moving on: Topics for the day

- Incremental updates
- Revisiting “trend” algorithms
- Generalization
- Tricks of the trade
  - Divergences..
  - Activations
  - Normalizations
• Given input output pairs at a number of locations, estimate the entire function
Gradient descent

- Start with an initial function

Gradient descent adjusts parameters to adjust the function value at all points and repeat this iteratively until we get arbitrarily close to the target function at the training points.
Gradient descent

- Start with an initial function
- Adjust its value at all points to make the outputs closer to the required value
  - Gradient descent adjusts parameters to adjust the function value at all points
  - Repeat this iteratively until we get arbitrarily close to the target function at the training points
Gradient descent

• Start with an initial function
• Adjust its value at *all* points to make the outputs closer to the required value
  – Gradient descent adjusts parameters to adjust the function value at *all* points
  – Repeat this iteratively until we get arbitrarily close to the target function at the training points
Gradient descent

• Start with an initial function
• Adjust its value at all points to make the outputs closer to the required value
  – Gradient descent adjusts parameters to adjust the function value at all points
  – Repeat this iteratively until we get arbitrarily close to the target function at the training points
Gradient descent

- Start with an initial function
- Adjust its value at *all* points to make the outputs closer to the required value
  - Gradient descent adjusts parameters to adjust the function value at *all* points
  - Repeat this iteratively until we get arbitrarily close to the target function at the training points
Effect of number of samples

- Problem with conventional gradient descent: we try to simultaneously adjust the function at *all* training points
  - We must process *all* training points before making a single adjustment
  - “Batch” update
Alternative: Incremental update

• Alternative: adjust the function at one training point at a time
  – Keep adjustments small
Alternative: Incremental update

• Alternative: adjust the function at one training point at a time
  – Keep adjustments small
Alternative: Incremental update

- Alternative: adjust the function at one training point at a time
  - Keep adjustments small
Alternative: Incremental update

• Alternative: adjust the function at one training point at a time
  – Keep adjustments small
• Alternative: adjust the function at one training point at a time
  – Keep adjustments small
  – Eventually, when we have processed all the training points, we will have adjusted the entire function
    • With greater overall adjustment than we would if we made a single “Batch” update
Incremental Update: Stochastic Gradient Descent

• Given \((X_1, d_1), (X_2, d_2), \ldots, (X_T, d_T)\)

• Initialize all weights \(W_1, W_2, \ldots, W_K\)

• Do:
  
  – For all \(t = 1: T\)
    
    • For every layer \(k\):
      
      – Compute \(\nabla_{W_k} \text{Div}(Y_t, d_t)\)
      
      – Update 
        \[
        W_k = W_k - \eta \nabla_{W_k} \text{Div}(Y_t, d_t)
        \]

• Until \(Err\) has converged
• If we loop through the samples in the same order, we may get cyclic behavior
Caveats: order of presentation

• If we loop through the samples in the same order, we may get cyclic behavior
• We must go through them randomly
Caveats: order of presentation

- If we loop through the samples in the same order, we may get cyclic behavior
Caveats: order of presentation

• If we loop through the samples in the same order, we may get cyclic behavior
Caveats: order of presentation

• If we loop through the samples in the same order, we may get cyclic behavior
Caveats: order of presentation

- If we loop through the samples in the same order, we may get cyclic behavior.
- We must go through them randomly to get more convergent behavior.
Caveats: learning rate

- Except in the case of a perfect fit, even an optimal overall fit will look incorrect to *individual* instances
  - Correcting the function for individual instances will lead to never-ending, non-convergent updates
  - We must *shrink* the learning rate with iterations to prevent this
    - Correction for individual instances with the eventual miniscule learning rates will not modify the function
Incremental Update: Stochastic Gradient Descent

• Given \((X_1, d_1), (X_2, d_2), ..., (X_T, d_T)\)
• Initialize all weights \(W_1, W_2, ..., W_K; \ j = 0\)
• Do:
  – Randomly permute \((X_1, d_1), (X_2, d_2), ..., (X_T, d_T)\)
  – For all \(t = 1: T\)
    • \(j = j + 1\)
    • For every layer \(k\):
      – Compute \(\nabla_{W_k} \text{Div}(Y_t, d_t)\)
      – Update
        \[ W_k = W_k - \eta_j \nabla_{W_k} \text{Div}(Y_t, d_t) \]
• Until \(Err\) has converged
Incremental Update: Stochastic Gradient Descent

- Given \((X_1, d_1), (X_2, d_2),..., (X_T, d_T)\)
- Initialize all weights \(W_1, W_2, ..., W_K; \ j = 0\)
- Do:
  - Randomly permute \((X_1, d_1), (X_2, d_2),..., (X_T, d_T)\)
  - For all \(t = 1: T\)
    - \(j = j + 1\)
    - For every layer \(k:\)
      - Compute \(\nabla_{W_k} \text{Div}(Y_t, d_t)\)
      - Update \(W_k = W_k - \eta_j \nabla_{W_k} \text{Div}(Y_t, d_t)\)
- Until \(\text{Err}\) has converged
Stochastic Gradient Descent

• The iterations can make multiple passes over the data

• A single pass through the entire training data is called an “epoch”
  – An epoch over a training set with $T$ samples results in $T$ updates of parameters
When does SGD work

• SGD converges “almost surely” to a global or local minimum for most functions
  – Sufficient condition: step sizes follow the following conditions
    \[ \sum_{k} \eta_k = \infty \]
    • Eventually the entire parameter space can be searched
    \[ \sum_{k} \eta_k^2 < \infty \]
    • The steps shrink
      – The fastest converging series that satisfies both above requirements is
        \[ \eta_k \propto \frac{1}{k} \]
        • This is the optimal rate of shrinking the step size for strongly convex functions
      – More generally, the learning rates are optimally determined
    • If the loss is convex, SGD converges to the optimal solution
    • For non-convex losses SGD converges to a local minimum
SGD convergence

• We will define convergence in terms of the number of iterations taken to get within $\epsilon$ of the optimal solution
  
  $|f(W^{(k)}) - f(W^*)| < \epsilon$

  – Note: $f(W)$ here is the error on the entire training data, although SGD itself updates after every training instance

• Using the optimal learning rate $1/k$, for strongly convex functions,

  $|W^{(k)} - W^*| < \frac{1}{k} |W^{(0)} - W^*|$

  – Giving us the iterations to $\epsilon$ convergence as $O\left(\frac{1}{\epsilon}\right)$

• For generically convex (but not strongly convex) function, various proofs report an $\epsilon$ convergence of $\frac{1}{\sqrt{k}}$ using a learning rate of $\frac{1}{\sqrt{k}}$. 
Batch gradient convergence

- In contrast, using the batch update method, for strongly convex functions,
  \[ |W^{(k)} - W^*| < c^k |W^{(0)} - W^*| \]
  - Giving us the iterations to \( \epsilon \) convergence as \( O \left( \log \left( \frac{1}{\epsilon} \right) \right) \)

- For generic convex functions, iterations to \( \epsilon \) convergence is \( O \left( \frac{1}{\epsilon} \right) \)

- Batch gradients converge "faster"
  - But SGD performs \( T \) updates for every batch update
SGD Convergence: Loss value

If:

• $f$ is $\lambda$-strongly convex, and
• at step $t$ we have a noisy estimate of the subgradient $\hat{g}_t$ with $\mathbb{E}[\|\hat{g}_t\|^2] \leq G^2$ for all $t$,
• and we use step size $\eta_t = 1/\lambda t$

Then for any $T > 1$:

$$\mathbb{E}[f(w_T) - f(w^*)] \leq \frac{17G^2(1 + \log(T))}{\lambda T}$$
SGD Convergence

• We can bound the expected difference between the loss over our data using the optimal weights $w^*$ and the weights $w_T$ at any single iteration to $O\left(\frac{\log(T)}{T}\right)$ for strongly convex loss or $O\left(\frac{\log(T)}{\sqrt{T}}\right)$ for convex loss.

• Averaging schemes can improve the bound to $O\left(\frac{1}{T}\right)$ and $O\left(\frac{1}{\sqrt{T}}\right)$.

• Smoothness of the loss is not required.
SGD Convergence and weight averaging

Polynomial Decay Averaging:

\[ \bar{w}_t^\gamma = \left( 1 - \frac{\gamma + 1}{t + \gamma} \right) \bar{w}_{t-1}^\gamma + \frac{\gamma + 1}{t + \gamma} w_t \]

With \( \gamma \) some small positive constant, e.g. \( \gamma = 3 \)

Achieves \( O \left( \frac{1}{T} \right) \) (strongly convex) and \( O \left( \frac{1}{\sqrt{T}} \right) \) (convex) convergence
SGD example

- A simpler problem: K-means
- Note: SGD converges slower
- Also note the rather large variation between runs
  - Let's try to understand these results.
Recall: Modelling a function

\[ Y = f(X; W) \]

- To learn a network \( f(X; W) \) to model a function \( g(X) \) we minimize the expected divergence

\[
\bar{W} = \arg\min_W \int_X \text{div}(f(X; W), g(X))P(X)dX
\]

\[ = \arg\min_W E[\text{div}(f(X; W), g(X))] \]
Recall: The *Empirical risk*

- In practice, we minimize the *empirical error*

\[
Err(f(X; W), g(X)) = \frac{1}{N} \sum_{i=1}^{N} \text{div}(f(X_i; W), d_i)
\]

\[
\hat{W} = \arg\min_{W} Err(f(X; W), g(X))
\]

- The *expected value* of the *empirical error* is actually the *expected divergence*

\[
E[Err(f(X; W), g(X))] = E[\text{div}(f(X; W), g(X))]
\]
Recap: The *Empirical* risk

- In practice, we minimize the *empirical error*

\[
\text{Err}(f(X; W), g(X)) = \frac{1}{N} \sum_{i=1}^{N} \text{div}(f(X_i; W), d_i)
\]

*The empirical error is an *unbiased* estimate of the expected error*

Though there is no guarantee that minimizing it will minimize the expected error

The expected value of the empirical error is actually the expected error

\[
E[\text{Err}(f(X; W), g(X))] = E[\text{div}(f(X; W), g(X))]
\]
Recap: The *Empirical risk*

In practice, we minimize the empirical error

\[
\text{Err} = \frac{1}{N} \sum_{i=1}^{N} \text{div}(f(X;W), d_i)
\]

The variance of the empirical error: \( \text{var}(\text{Err}) = \frac{1}{N} \text{var}(\text{div}) \)

The variance of the estimator is proportional to \( \frac{1}{N} \)

The larger this variance, the greater the likelihood that the \( W \) that minimizes the empirical error will differ significantly from the \( W \) that minimizes the expected error

The empirical error is an *unbiased* estimate of the expected error

Though there is no guarantee that minimizing it will minimize the expected error

\[
E[\text{Err}(f(X;W), g(X))] = E[\text{div}(f(X;W), g(X))]
\]
At each iteration, SGD focuses on the divergence of a single sample \( \text{div}(f(X_i; W), d_i) \).

The expected value of the sample error is still the expected divergence \( E[\text{div}(f(X; W), g(X))] \).
At each iteration, SGD focuses on the divergence of a single sample $\text{div}(f(X_i; W), d_i)$

The expected value of the sample error is still the expected divergence $E[\text{div}(f(X; W), g(X))]$
At each iteration, **SGD** focuses on the divergence of a single sample \( \text{div}(f(X_i; W), d_i) \).

The variance of the sample error is the variance of the divergence itself: \( \text{var(div)} \). This is \( N \) times the variance of the empirical average minimized by batch update.

The sample error is also an unbiased estimate of the expected error:

\[
E[\text{div}(f(X; W), g(X))]
\]
Explaining the variance

- The blue curve is the function being approximated
- The red curve is the approximation by the model at a given $W$
- The heights of the shaded regions represent the point-by-point error
  - The divergence is a function of the error
  - We want to find the $W$ that minimizes the average divergence
Explaining the variance

- Sample estimate approximates the shaded area with the average length of the lines
Explaining the variance

- Sample estimate approximates the shaded area with the average length of the lines
- This average length will change with position of the samples
Explaining the variance

- Sample estimate approximates the shaded area with the average length of the lines
- This average length will change with position of the samples
• Having more samples makes the estimate more robust to changes in the position of samples
  – The variance of the estimate is smaller
Explaining the variance

• Having very few samples makes the estimate swing wildly with the sample position
  – Since our estimator learns the $W$ to minimize this estimate, the learned $W$ too can swing wildly
Explaining the variance

- Having very few samples makes the estimate swing wildly with the sample position
  - Since our estimator learns the $W$ to minimize this estimate, the learned $W$ too can swing wildly
Explaining the variance

- Having very few samples makes the estimate swing wildly with the sample position
  - Since our estimator learns the $W$ to minimize this estimate, the learned $W$ too can swing wildly
SGD example

- A simpler problem: K-means
- Note: SGD converges slower
- Also has large variation between runs
SGD vs batch

- SGD uses the gradient from only one sample at a time, and is consequently high variance

- But also provides significantly quicker updates than batch

- Is there a good medium?
Alternative: adjust the function at a small, randomly chosen subset of points
  – Keep adjustments small
  – If the subsets cover the training set, we will have adjusted the entire function
• As before, vary the subsets randomly in different passes through the training data
Incremental Update: Mini-batch update

- Given \((X_1, d_1), (X_2, d_2),..., (X_T, d_T)\)
- Initialize all weights \(W_1, W_2, ..., W_K; \ j = 0\)
- Do:
  - Randomly permute \((X_1, d_1), (X_2, d_2),..., (X_T, d_T)\)
  - For \(t = 1:b:T\)
    - \(j = j + 1\)
    - For every layer \(k:\)
      - \(\Delta W_k = 0\)
    - For \(t' = t : t+b-1\)
      - For every layer \(k:\)
        » Compute \(\nabla_{W_k} Div(Y_t, d_t)\)
        » \(\Delta W_k = \Delta W_k + \nabla_{W_k} Div(Y_t, d_t)\)
    - Update
      - For every layer \(k:\)
        \[W_k = W_k - \eta_j \Delta W_k\]
- Until \(Err\) has converged
Incremental Update: **Mini-batch update**

- Given \((X_1, d_1), (X_2, d_2), \ldots, (X_T, d_T)\)
- Initialize all weights \(W_1, W_2, \ldots, W_K; \ j = 0\)
- Do:
  - Randomly permute \((X_1, d_1), (X_2, d_2), \ldots, (X_T, d_T)\)
  - For \(t = 1:b:T\)
    - \(j = j + 1\)
    - For every layer \(k:\)
      - \(\Delta W_k = 0\)
    - For \(t' = t : t+b-1\)
      - For every layer \(k:\)
        » Compute \(\nabla_{W_k} \text{Div}(Y_t, d_t)\)
        » \(\Delta W_k = \Delta W_k + \nabla_{W_k} \text{Div}(Y_t, d_t)\)
  - Update
    - For every layer \(k:\)
      \[
      W_k = W_k - \eta_j \Delta W_k
      \]
- Until \(Err\) has converged
Mini Batches

- Mini-batch updates compute and minimize a *batch error*

\[
BatchErr(f(X; W), g(X)) = \frac{1}{b} \sum_{i=1}^{b} \text{div}(f(X_i; W), d_i)
\]

- The *expected value* of the *batch error* is also the *expected divergence*

\[
E[BatchErr(f(X; W), g(X))] = E[\text{div}(f(X; W), g(X))]
\]
Mini Batches

- Mini-batch updates computes an empirical batch error

\[ \text{BatchErr}(f(X;W), g(X)) = \frac{1}{b} \sum_{i=1}^{b} \text{div}(f(X_i;W), d_i) \]

- The expected value of the batch error is also the expected divergence

\[ E[\text{BatchErr}(f(X;W), g(X))] = E[\text{div}(f(X;W), g(X))] \]
Mini Batches

- Mini-batch updates computes an empirical batch error
  \[ \frac{1}{b} \sum_{i=1}^{b} \text{div}(f(X_i; W), d_i) \]

The variance of the batch error: \( \text{var(Err)} = \frac{1}{b} \text{var(div)} \)
This will be much smaller than the variance of the sample error in SGD

The batch error is also an unbiased estimate of the expected error

- The expected value of the batch error is also the expected divergence
  \[ E[\text{BatchErr}(f(X; W), g(X))] = E[\text{div}(f(X; W), g(X))] \]
Minibatch convergence

• For convex functions, convergence rate for SGD is $O\left(\frac{1}{\sqrt{k}}\right)$.

• For *mini-batch* updates with batches of size $b$, the convergence rate is $O\left(\frac{1}{\sqrt{bk}} + \frac{1}{k}\right)$
  – Apparently an improvement of $\sqrt{b}$ over SGD
  – But since the batch size is $b$, we perform $b$ times as many computations per iteration as SGD
  – We actually get a *degradation* of $\sqrt{b}$

• However, in practice
  – The objectives are generally not convex; mini-batches are more effective with the right learning rates
  – We also get additional benefits of vector processing
• Mini-batch performs comparably to batch training on this simple problem
  – But converges orders of magnitude faster
Measuring Error

• Convergence is generally defined in terms of the *overall training error*
  – Not sample or batch error

• Infeasible to actually measure the overall training error after each iteration

• More typically, we estimate it as
  – Divergence or classification error on a held-out set
  – Average sample/batch error over the past $N$ samples/batches
Training and minibatches

• In practice, training is usually performed using minibatches
  – The mini-batch size is a hyper parameter to be optimized

• Convergence depends on learning rate
  – Simple technique: fix learning rate until the error plateaus, then reduce learning rate by a fixed factor (e.g. 10)
  – **Advanced methods**: Adaptive updates, where the learning rate is itself determined as part of the estimation
Training and minibatches

• In practice, training is usually performed using minibatches
  – The mini-batch size is a hyper parameter to be optimized

• Convergence depends on learning rate
  – Simple technique: fix learning rate until the error plateaus, then reduce learning rate by a fixed factor (e.g. 10)
  – Advanced methods: Adaptive updates, where the learning rate is itself determined as part of the estimation
Moving on: Topics for the day

• Incremental updates

• Revisiting “trend” algorithms

• Generalization

• Tricks of the trade
  – Divergences..
  – Activations
  – Normalizations
Recall: Momentum

- The momentum method
  \[ \Delta W^{(k)} = \beta \Delta W^{(k-1)} + \eta \nabla_W \text{Err}(W^{(k-1)}) \]
- Updates using a running average of the gradient
Momentum and incremental updates

- The momentum method
  \[ \Delta W^{(k)} = \beta \Delta W^{(k-1)} + \eta \nabla W \text{Err}(W^{(k-1)}) \]
- Incremental SGD and mini-batch gradients tend to have high variance
- Momentum smooths out the variations
  - Smoother and faster convergence
Training with momentum

- Initialize all weights $W_1, W_2, \ldots, W_K$
- Do:
  - For all layers $k$, initialize $\nabla_{W_k} Err = 0, \Delta W_k = 0$
  - For all $t = 1: T$
    - For every layer $k$:
      - Compute gradient $\nabla_{W_k} \text{Div}(Y_t, d_t)$
      - $\nabla_{W_k} Err += \nabla_{W_k} \text{Div}(Y_t, d_t)$
  - For every layer $k$
    \[ \Delta W_k = \beta \Delta W_k + \eta \nabla_{W_k} Err \]
    \[ W_k = W_k - \Delta W_k \]
- Until $Err$ has converged
Nestorov’s Accelerated Gradient

• At any iteration, to compute the current step:
  – First extend the previous step
  – Then compute the gradient at the resultant position
  – Add the two to obtain the final step

• This also applies directly to incremental update methods
  – The accelerated gradient smooths out the variance in the gradients
Nestorov’s Accelerated Gradient

- Nestorov’s method

\[ \Delta W^{(k)} = \beta \Delta W^{(k-1)} + \eta \nabla_{W} Err(W^{(k-1)} - \beta \Delta W^{(k-1)}) \]

\[ W^{(k)} = W^{(k-1)} - \Delta W^{(k)} \]
Training with Nestorov’s

• Initialize all weights $W_1, W_2, \ldots, W_K$

• Do:
  – For all layers $k$, initialize $\nabla_{W_k} Err = 0, \Delta W_k = 0$
  – For every layer $k$
    $$W_k = W_k - \beta \Delta W_k$$
  – For all $t = 1:T$
    • For every layer $k$:
      – Compute gradient $\nabla_{W_k} \text{Div}(Y_t, d_t)$
      – $\nabla_{W_k} \text{Err} += \nabla_{W_k} \text{Div}(Y_t, d_t)$
    – For every layer $k$
      $$W_k = W_k - \eta \nabla_{W_k} Err$$
      $$\Delta W_k = \beta \Delta W_k + \eta \nabla_{W_k} Err$$

• Until $Err$ has converged
More recent methods

• Several newer methods have been proposed that follow the general pattern of enhancing long-term trends to smooth out the variations of the mini-batch gradient
  – RMS Prop
  – ADAM: very popular in practice
  – Adagrad
  – AdaDelta
  – ...

• All roughly equivalent in performance
Smoothing the trajectory

- Simple gradient and acceleration methods still demonstrate oscillatory behavior in some directions
- Observation: Steps in “oscillatory” directions show large total movement
  - In the example, total motion in the vertical direction is much greater than in the horizontal direction
- Improvement: Dampen step size in directions with high motion
  - *Second order term*

<table>
<thead>
<tr>
<th>Step</th>
<th>X component</th>
<th>Y component</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>+2.5</td>
</tr>
<tr>
<td>2</td>
<td>1</td>
<td>-3</td>
</tr>
<tr>
<td>3</td>
<td>3</td>
<td>+2.5</td>
</tr>
<tr>
<td>4</td>
<td>1</td>
<td>-2</td>
</tr>
<tr>
<td>5</td>
<td>2</td>
<td>1.5</td>
</tr>
</tbody>
</table>
Variance-normalized step

- In recent past
  - Total movement in $Y$ component of updates is high
  - Movement in $X$ components is lower
- Current update, modify usual gradient-based update:
  - Scale down $Y$ component
  - Scale up $X$ component
  - According to their variation (and not just their average)
- A variety of algorithms have been proposed on this premise
  - We will see a popular example
RMS Prop

• Notation:
  – Updates are *by parameter*
  
  – Sum derivative of divergence w.r.t any individual parameter $w$ is shown as $\partial_w D$

  – The *squared* derivative is $\partial^2_w D = (\partial_w D)^2$

  – The *mean squared* derivative is a running estimate of the average squared derivative. We will show this as $E[\partial^2_w D]$

• Modified update rule: We want to
  – scale down updates with large mean squared derivatives
  – scale up updates with small mean squared derivatives
RMS Prop

• This is a variant on the basic mini-batch SGD algorithm

• Procedure:
  – Maintain a running estimate of the mean squared value of derivatives for each parameter
  – Scale update of the parameter by the inverse of the root mean squared derivative

\[
E[\partial_w^2 D]_k = \gamma E[\partial_w^2 D]_{k-1} + (1 - \gamma) (\partial_w^2 D)_k
\]

\[
w_{k+1} = w_k - \frac{\eta}{\sqrt{E[\partial_w^2 D]_k + \epsilon}} \partial_w D
\]
RMS Prop (updates are for each weight of each layer)

• Do:
  – Randomly shuffle inputs to change their order
  – Initialize: $k = 1$; for all weights $w$ in all layers, $E[\partial_w^2D]_k = 0$
  – For all $t = 1: B: T$ (incrementing in blocks of $B$ inputs)
    • For all weights in all layers initialize $(\partial_wD)_k = 0$
    • For $b = 0: B - 1$
      – Compute
        » Output $Y(X_{t+b})$
        » Compute gradient $\frac{dDiv(Y(X_{t+b}),d_{t+b})}{dw}$
        » Compute $(\partial_wD)_k += \frac{dDiv(Y(X_{t+b}),d_{t+b})}{dw}$

• update:

\[
E[\partial_w^2D]_k = \gamma E[\partial_w^2D]_{k-1} + (1 - \gamma)(\partial_w^2D)_k
\]

\[
w_{k+1} = w_k - \eta \frac{\partial_wD}{\sqrt{E[\partial_w^2D]_k + \epsilon}}
\]

• $k = k + 1$

• Until $E(W^{(1)}, W^{(2)}, \ldots, W^{(K)})$ has converged
Other variants of the same theme

• Many:
  – Adagrad
  – AdaDelta
  – ADAM
  – AdaMax
  – ...

• Note: no need to decide a learning rate schedule
  – Automatically updated
  – It’s not even necessary to set the initial learning rate $\eta$ in most cases
    • Setting it to 1.0 works just fine
Visualizing the optimizers: Beale’s Function

Visualizing the optimizers: Long Valley

Visualizing the optimizers: Saddle Point

Story so far

• Gradient descent can be sped up by incremental updates
  – Convergence is guaranteed under most conditions
  – Stochastic gradient descent: update after each observation. Can be much faster than batch learning
  – Mini-batch updates: update after batches. Can be more efficient than SGD

• Convergence can be improved using smoothed updates
  – RMSprop and more advanced techniques
Moving on: Topics for the day

- Incremental updates
- Revisiting “trend” algorithms
- Generalization
- Tricks of the trade
  - Divergences..
  - Activations
  - Normalizations
Tricks of the trade..

- To make the network converge better
  - The Divergence
  - Dropout
  - Batch normalization
  - Other tricks
    - Gradient clipping
    - Data augmentation
    - Other hacks..
Training Neural Nets by Gradient Descent: The Divergence

Total training error:

\[ Err = \frac{1}{T} \sum_t \text{Div}(Y_t, d_t; W_1, W_2, \ldots, W_K) \]

• The convergence of the gradient descent depends on the divergence
  – Ideally, must have a shape that results in a significant gradient in the right direction outside the optimum
  • To “guide” the algorithm to the right solution
Desiderata for a good divergence

- Must be smooth and not have many poor local optima
- Low slopes far from the optimum == bad
  - Initial estimates far from the optimum will take forever to converge
- High slopes near the optimum == bad
  - Steep gradients
Desiderata for a good divergence

- Functions that are shallow far from the optimum will result in very small steps during optimization
  - Slow convergence of gradient descent
- Functions that are steep near the optimum will result in large steps and overshoot during optimization
  - Gradient descent will not converge easily
- The best type of divergence is steep far from the optimum, but shallow at the optimum
  - But not too shallow: ideally quadratic in nature
Choices for divergence

**Most common choices:** The L2 divergence and the KL divergence

<table>
<thead>
<tr>
<th>Desired output:</th>
<th>d</th>
<th>Desired output:</th>
<th>([0,0, ..., 1, ..., 0])</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>L2</strong></td>
<td>(Div = (y - d)^2)</td>
<td>(Div = \sum_i (y_i - d_i)^2)</td>
<td></td>
</tr>
<tr>
<td><strong>KL</strong></td>
<td>(Div = d \log(y) + (1 - d) \log(1 - y))</td>
<td>(Div = \sum_i d_i \log(y_i))</td>
<td></td>
</tr>
</tbody>
</table>

\[122\]
L2 or KL?

- The L2 divergence has long been favored in most applications
- It is particularly appropriate when attempting to perform regression
  - Numeric prediction
- The KL divergence is better when the intent is classification
  - The output is a probability vector
L2 or KL

- Plot of L2 and KL divergences for a single perceptron, as function of weights
  - Setup: 2-dimensional input
  - 100 training examples randomly generated
The problem of covariate shifts

• Training assumes the training data are all similarly distributed
  – Minibatches have similar distribution
The problem of covariate shifts

• Training assumes the training data are all similarly distributed
  – Minibatches have similar distribution
• In practice, each minibatch may have a different distribution
  – A “covariate shift”
  – Which may occur in each layer of the network
The problem of covariate shifts

- Training assumes the training data are all similarly distributed
  - Minibatches have similar distribution
- In practice, each minibatch may have a different distribution
  - A “covariate shift”
- Covariate shifts can be large!
  - All covariate shifts can affect training badly
Solution: Move all subgroups to a “standard” location

- “Move” all batches to have a mean of 0 and unit standard deviation
  - Eliminates covariate shift between batches
Solution: Move all subgroups to a “standard” location

• “Move” all batches to have a mean of 0 and unit standard deviation
  – Eliminates covariate shift between batches
Solution: Move all subgroups to a “standard” location

• “Move” all batches to have a mean of 0 and unit standard deviation
  –Eliminates covariate shift between batches
Solution: Move all subgroups to a “standard” location

• “Move” all batches to have a mean of 0 and unit standard deviation
  – Eliminates covariate shift between batches
Solution: Move all subgroups to a “standard” location

- “Move” all batches to have a mean of 0 and unit standard deviation
  - Eliminates covariate shift between batches
Solution: Move all subgroups to a “standard” location

• “Move” all batches to have a mean of 0 and unit standard deviation
  – Eliminates covariate shift between batches
  – Then move the entire collection to the appropriate location
Batch normalization

- Batch normalization is a covariate adjustment unit that happens after the weighted addition of inputs but before the application of activation
  - Is done independently for each unit, to simplify computation
- **Training:** The adjustment occurs over individual minibatches
Batch normalization

- BN aggregates the statistics over a minibatch and normalizes the batch by them.
- Normalized instances are “shifted” to a *unit-specific* location.
Batch normalization: Training

\[ z = \sum_{j} w_j i_j + b \]

- BN aggregates the statistics over a minibatch and normalizes the batch by them.
- Normalized instances are “shifted” to a unit-specific location.
Batch normalization: Training

- **BN aggregates the statistics over a minibatch and normalizes the batch by them**
- **Normalized instances are “shifted” to a *unit-specific* location**

\[ z = \sum_j w_j i_j + b \]

\[
\mu_B = \frac{1}{B} \sum_{i=1}^{B} z_i \\
\sigma_B^2 = \frac{1}{B} \sum_{i=1}^{B} (z_i - \mu_B)^2 \\
u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}} \\
\hat{z}_i = \gamma u_i + \beta
\]
Batch normalization: Training

• BN aggregates the statistics over a minibatch and normalizes the batch by them
• Normalized instances are “shifted” to a unit-specific location
A better picture for batch norm
Batch normalization: Backpropagation

\[ \frac{d\text{Div}}{d\hat{z}} = f'(\hat{z}) \frac{d\text{Div}}{dy} \]

\[ \hat{z}_i = y u_i + \beta \]

\[ u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}} \]

\[ \mu_B = \frac{1}{B} \sum_{i=1}^{B} z_i \]

\[ \sigma_B^2 = \frac{1}{B} \sum_{i=1}^{B} (z_i - \mu_B)^2 \]
Batch normalization: Backpropagation

\[ \frac{d\text{Div}}{d\beta} = \frac{d\text{Div}}{d\hat{z}} \]

\[ \frac{d\text{Div}}{dy} = u \frac{d\text{Div}}{d\hat{z}} \]

\[ \frac{d\text{Div}}{d\hat{z}} = f'(\hat{z}) \frac{d\text{Div}}{dy} \]

Parameters to be learned

\[ u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}} \]

\[ \hat{z}_i = \gamma u_i + \beta \]

\[ \mu_B = \frac{1}{B} \sum_{i=1}^{B} z_i \]

\[ \sigma_B^2 = \frac{1}{B} \sum_{i=1}^{B} (z_i - \mu_B)^2 \]
Batch normalization: Backpropagation

Parameters to be learned

\[
\frac{d \text{Div}}{d \beta} = \frac{d \text{Div}}{d \hat{z}}
\]

\[
\frac{d \text{Div}}{d \gamma} = \mu \frac{d \text{Div}}{d \hat{z}}
\]

\[
\frac{d \text{Div}}{du} = \gamma \frac{d \text{Div}}{d \hat{z}}
\]

\[
\frac{d \text{Div}}{d \hat{z}} = f'(\hat{z}) \frac{d \text{Div}}{dy}
\]

\[
u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}}
\]

\[
\hat{z}_i = \gamma u_i + \beta
\]

\[
\mu_B = \frac{1}{B} \sum_{i=1}^{B} z_i
\]

\[
\sigma_B^2 = \frac{1}{B} \sum_{i=1}^{B} (z_i - \mu_B)^2
\]
Batch normalization: Backpropagation

\[
\frac{\partial \text{Div}}{\partial \sigma_B^2} = \sum_{i=1}^{B} \frac{\partial \text{Div}}{\partial u_i} (z_i - \mu_B) \cdot \frac{-1}{2} (\sigma_B^2 + \epsilon)^{-3/2}
\]

\[
\sigma_B^2 = \frac{1}{B} \sum_{i=1}^{B} (z_i - \mu_B)^2
\]

\[
\mu_B = \frac{1}{B} \sum_{i=1}^{B} z_i
\]

\[
u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}} \quad \hat{z}_i = \gamma u_i + \beta
\]
Batch normalization: Backpropagation

\[ \frac{\partial \text{Div}}{\partial \sigma_B^2} = \sum_{i=1}^{B} \frac{\partial \text{Div}}{\partial u_i} (z_i - \mu_B) \cdot \frac{-1}{2} \left( \sigma_B^2 + \epsilon \right)^{-3/2} \]

Influence diagram

\[ u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}} \quad \hat{z}_i = \gamma u_i + \beta \]
Batch normalization:
Backpropagation

\[
\frac{\partial \text{Div}}{\partial \sigma_B^2} = \sum_{i=1}^{B} \frac{\partial \text{Div}}{\partial u_i} (z_i - \mu_B) \cdot \frac{-1}{2} \left(\sigma_B^2 + \epsilon\right)^{-3/2}
\]

\[
\frac{\partial \text{Div}}{\partial \mu_B} = \left( \sum_{i=1}^{B} \frac{\partial \text{Div}}{\partial u_i} \cdot \frac{-1}{\sqrt{\sigma_B^2 + \epsilon}} \right) + \frac{\partial \text{Div}}{\partial \sigma_B^2} \cdot \frac{\sum_{i=1}^{B} -2(z_i - \mu_B)}{B}
\]

\[
\mu_B = \frac{1}{B} \sum_{i=1}^{B} z_i
\]

\[
\sigma_B^2 = \frac{1}{B} \sum_{i=1}^{B} (z_i - \mu_B)^2
\]

\[
u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}}
\]

\[
\hat{z}_i = \gamma u_i + \beta
\]
Batch normalization: Backpropagation

\[
\frac{\partial \text{Div}}{\partial \sigma_B^2} = \sum_{i=1}^{B} \frac{\partial \text{Div}}{\partial u_i} (z_i - \mu_B) \cdot -\frac{1}{2} (\sigma_B^2 + \epsilon)^{-3/2}
\]

\[
\frac{\partial \text{Div}}{\partial \mu_B} = \left( \sum_{i=1}^{B} \frac{\partial \text{Div}}{\partial u_i} \cdot -\frac{1}{\sqrt{\sigma_B^2 + \epsilon}} \right) + \frac{\partial \text{Div}}{\partial \sigma_B^2} \cdot \frac{\sum_{i=1}^{B} -2(z_i - \mu_B)}{B}
\]

\[
\mu_B = \frac{1}{B} \sum_{i=1}^{B} z_i
\]

\[
\sigma_B^2 = \frac{1}{B} \sum_{i=1}^{B} (z_i - \mu_B)^2
\]

Influence diagram
Batch normalization:
Backpropagation

\[
\frac{\partial \text{Div}}{\partial \sigma_B^2} = \sum_{i=1}^{B} \frac{\partial \text{Div}}{\partial u_i} (z_i - \mu_B) \cdot \frac{-1}{2} (\sigma_B^2 + \epsilon)^{-3/2}
\]

\[
\frac{\partial \text{Div}}{\partial \mu_B} = \left( \sum_{i=1}^{B} \frac{\partial \text{Div}}{\partial u_i} \cdot \frac{-1}{\sqrt{\sigma_B^2 + \epsilon}} \right) + \frac{\partial \text{Div}}{\partial \sigma_B^2} \cdot \frac{\sum_{i=1}^{B} -2(z_i - \mu_B)}{B}
\]

\[
\frac{\partial \text{Div}}{\partial z_i} = \frac{1}{\sigma_B^2 + \epsilon} \frac{\partial \text{Div}}{\partial u_i} + \frac{2(z_i - \mu_B)}{B} \frac{\partial \text{Div}}{\partial \sigma_B^2} + \frac{1}{B} \frac{\partial \text{Div}}{\partial \mu_B}
\]

\[
\mu_B = \frac{1}{B} \sum_{i=1}^{B} z_i
\]

\[
\sigma_B^2 = \frac{1}{B} \sum_{i=1}^{B} (z_i - \mu_B)^2
\]

\[
u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}}
\]

\[
\hat{z}_i = \gamma u_i + \beta
\]
Batch normalization:
Backpropagation

\[
\begin{align*}
\frac{\partial \text{Div}}{\partial \sigma_B^2} &= \sum_{i=1}^B \frac{\partial \text{Div}}{\partial u_i} (z_i - \mu_B) \cdot \frac{-1}{2} \frac{1}{(\sigma_B^2 + \epsilon)^{3/2}} \\
\frac{\partial \text{Div}}{\partial \mu_B} &= \left( \sum_{i=1}^B \frac{\partial \text{Div}}{\partial u_i} \cdot \frac{-1}{\sqrt{\sigma_B^2 + \epsilon}} \right) + \frac{\partial \text{Div}}{\partial \sigma_B^2} \cdot \sum_{i=1}^B z_i
\end{align*}
\]

\[
\frac{\partial \text{Div}}{\partial z_i} = \frac{\partial \text{Div}}{\partial u_i} \cdot \frac{1}{\sqrt{\sigma_B^2 + \epsilon}} + \frac{\partial \text{Div}}{\partial \sigma_B^2} \cdot \frac{2(z_i - \mu_B)}{B} + \frac{\partial \text{Div}}{\partial \mu_B} \cdot \frac{1}{B}
\]

\[
\mu_B = \frac{1}{B} \sum_{i=1}^B z_i \\
\sigma_B^2 = \frac{1}{B} \sum_{i=1}^B (z_i - \mu_B)^2
\]

\[
u_i = \frac{z_i - \mu_B}{\sqrt{\sigma_B^2 + \epsilon}}
\]

\[
\hat{z}_i = \gamma u_i + \beta
\]
Batch normalization: Backpropagation

\[
\frac{\partial D_{iv}}{\partial \sigma_B^2} = \sum_{i=1}^{B} \frac{\partial D_{iv}}{\partial u_i} (z_i - \mu_B) \cdot \frac{-1}{2} (\sigma_B^2 + \epsilon)^{-3/2}
\]

\[
\frac{\partial D_{iv}}{\partial \mu_B} = \left( \sum_{i=1}^{B} \frac{\partial D_{iv}}{\partial u_i} \cdot \frac{-1}{\sqrt{\sigma_B^2 + \epsilon}} \right) + \frac{\partial D_{iv}}{\partial \sigma_B^2} \cdot \frac{\sum_{i=1}^{B} -2(z_i - \mu_B)}{B}
\]

\[
\frac{\partial D_{iv}}{\partial z_i} = \frac{\partial D_{iv}}{\partial u_i} \cdot \frac{1}{\sqrt{\sigma_B^2 + \epsilon}} + \frac{\partial D_{iv}}{\partial \sigma_B^2} \cdot \frac{2(z_i - \mu_B)}{B} + \frac{\partial D_{iv}}{\partial \mu_B} \cdot \frac{1}{B}
\]

The rest of backprop continues from \( \frac{\partial D_{iv}}{\partial z_i} \)
Batch normalization: Inference

- On test data, BN requires $\mu_B$ and $\sigma_{BN}^2$.
- We will use the average over all training minibatches

$$
\mu_{BN} = \frac{1}{N_{batches}} \sum_{batch} \mu_B(batch)
$$

$$
\sigma_{BN}^2 = \frac{B}{(B-1)N_{batches}} \sum_{batch} \sigma_B^2(batch)
$$

- Note: these are neuron-specific
  - $\mu_B(batch)$ and $\sigma_B^2(batch)$ here are obtained from the final converged network
  - The $B/(B-1)$ term gives us an unbiased estimator for the variance
Batch normalization may only be applied to some layers
  – Or even only selected neurons in the layer

Improves both convergence rate and neural network performance
  – Anecdotal evidence that BN eliminates the need for dropout
  – To get maximum benefit from BN, learning rates must be increased and learning rate decay can be faster
    • Since the data generally remain in the high-gradient regions of the activations
  – Also needs better randomization of training data order
Batch Normalization: Typical result

- Performance on Imagenet, from Ioffe and Szegedy, JMLR 2015
The problem of data underspecification

• The figures shown so far were *fake news*..
Learning the network

• We attempt to learn an entire function from just a few *snapshots* of it
General approach to training

- Define an \textit{error} between the \textit{actual} network output for any parameter value and the \textit{desired} output
  - Error typically defined as the \textit{sum} of the squared error over individual training instances

\[ E = \sum_i (y_i - f(x_i, W))^2 \]
• Problem: Network may just learn the values at the inputs
  – Learn the red curve instead of the dotted blue one
    • Given only the red vertical bars as inputs
Data under-specification

- Consider a binary 100-dimensional input
- There are $2^{100} = 10^{30}$ possible inputs
- Complete specification of the function will require specification of $10^{30}$ output values
- A training set with only $10^{15}$ training instances will be off by a factor of $10^{15}$
Consider a binary 100-dimensional input
There are $2^{100}=10^{30}$ possible inputs
Complete specification of the function will require specification of $10^{30}$ output values
A training set with only $10^{15}$ training instances will be off by a factor of $10^{15}$
Need “smoothing” constraints

- Need additional constraints that will “fill in” the missing regions acceptably
  - Generalization
Smoothness through weight manipulation

• Illustrative example: Simple binary classifier
  – The “desired” output is generally smooth
Smoothness through weight manipulation

Illustrative example: Simple binary classifier
- The “desired” output is generally smooth
  - Capture statistical or average trends
- An unconstrained model will model individual instances instead
The unconstrained model

- Illustrative example: Simple binary classifier
  - The “desired” output is generally smooth
    - Capture statistical or average trends
  - An unconstrained model will model individual instances instead
Why overfitting

These sharp changes happen because..

..the perceptrons in the network are individually capable of sharp changes in output
The individual perceptron

- Using a sigmoid activation
  - As $|w|$ increases, the response becomes steeper
Smoothness through weight manipulation

- Steep changes that enable overfitted responses are facilitated by perceptrons with large \( w \)
Smoothness through weight manipulation

• Steep changes that enable overfitted responses are facilitated by perceptrons with large $w$

• Constraining the weights $w$ to be low will force slower perceptrons and smoother output response
Objective function for neural networks

- Conventional training: minimize the total error:

\[
Err(W_1, W_2, ..., W_K) = \frac{1}{T} \sum_t Div(Y_t, d_t; W_1, W_2, ..., W_K)
\]

- Batch training error:

\[
Div(Y_t, d_t; W_1, W_2, ..., W_K)
\]

- Desired output of network: \(d_t\)

\[
\widehat{W}_1, \widehat{W}_2, ..., \widehat{W}_K = \arg\min_{W_1, W_2, ..., W_K} Err(W_1, W_2, ..., W_K)
\]
Smoothness through weight constraints

- Regularized training: minimize the error while also minimizing the weights

\[ L(W_1, W_2, ..., W_K) = Err(W_1, W_2, ..., W_K) + \frac{1}{2} \lambda \sum_k \|W_k\|_2^2 \]

\[ \widehat{W}_1, \widehat{W}_2, ..., \widehat{W}_K = \underset{w_1, w_2, ..., w_K}{\text{argmin}} \ L(W_1, W_2, ..., W_K) \]

- \( \lambda \) is the regularization parameter whose value depends on how important it is for us to want to minimize the weights

- Increasing \( \lambda \) assigns greater importance to shrinking the weights
  - Make greater error on training data, to obtain a more acceptable network
Regularizing the weights

\[ L(W_1, W_2, ..., W_K) = \frac{1}{T} \sum_t \text{Div}(Y_t, d_t) + \frac{1}{2} \lambda \sum_k \|W_k\|_2^2 \]

- **Batch mode:**
  \[ \Delta W_k = \frac{1}{T} \sum_t \nabla_{W_k} \text{Div}(Y_t, d_t)^T + \lambda W_k \]

- **SGD:**
  \[ \Delta W_k = \nabla_{W_k} \text{Div}(Y_t, d_t)^T + \lambda W_k \]

- **Minibatch:**
  \[ \Delta W_k = \frac{1}{b} \sum_{\tau=t}^{t+b-1} \nabla_{W_k} \text{Div}(Y_{\tau}, d_{\tau})^T + \lambda W_k \]

- **Update rule:**
  \[ W_k \leftarrow W_k - \eta \Delta W_k \]
Incremental Update: Mini-batch update

- Given \((X_1, d_1), (X_2, d_2),..., (X_T, d_T)\)
- Initialize all weights \(W_1, W_2, ..., W_K\); \(j = 0\)

Do:
- Randomly permute \((X_1, d_1), (X_2, d_2),..., (X_T, d_T)\)
- For \(t = 1:b:T\)
  - \(j = j + 1\)
  - For every layer \(k\):
    - \(\Delta W_k = 0\)
  - For \(t' = t : t+b-1\)
    - For every layer \(k\):
      » Compute \(\nabla_{W_k} \text{Div}(Y_t, d_t)\)
      » \(\Delta W_k = \Delta W_k + \nabla_{W_k} \text{Div}(Y_t, d_t)\)
  - Update
    - For every layer \(k\):
      \[W_k = W_k - \eta_j (\Delta W_k + \lambda W_k)\]
- Until \(Err\) has converged
Smoothness through network structure

- MLPs naturally impose constraints
- MLPs are universal approximators
  - Arbitrarily increasing size can give you arbitrarily wiggly functions
  - The function will remain ill-defined on the majority of the space
- For a given number of parameters deeper networks impose more smoothness than shallow ones
  - Each layer works on the already smooth surface output by the previous layer
Even when we get it all right

- Typical results (varies with initialization)
- 1000 training points Many orders of magnitude more than you usually get
- All the training tricks known to mankind
But depth and training data help

- Deeper networks seem to learn better, for the same number of total neurons
  - *Implicit smoothness constraints*
    - As opposed to explicit constraints from more conventional classification models
- Similar functions not learnable using more usual pattern-recognition models!!

10000 training instances
Regularization..

• Other techniques have been proposed to improve the smoothness of the learned function
  – $L_1$ regularization of network activations
  – Regularizing with added noise..

• Possibly the most influential method has been “dropout”
A brief detour.. Bagging

• Popular method proposed by Leo Breiman:
  – Sample training data and train several different classifiers
  – Classify test instance with entire ensemble of classifiers
  – Vote across classifiers for final decision
  – Empirically shown to improve significantly over training a single classifier from combined data

• Returning to our problem....
Dropout

- **During training:** For each input, at each iteration, “turn off” each neuron with a probability $1-\alpha$
• **During training:** For each input, at each iteration, “turn off” each neuron with a probability $1 - \alpha$
  – Also turn off inputs similarly
• During training: For each input, at each iteration, “turn off” each neuron (including inputs) with a probability $1-\alpha$
  – In practice, set them to 0 according to the success of a Bernoulli random number generator with success probability $1-\alpha$
Dropout

- **During training:** For each input, at each iteration, “turn off” each neuron (including inputs) with a probability $1-\alpha$
  - In practice, set them to 0 according to the success of a Bernoulli random number generator with success probability $1-\alpha$
**Dropout**

During training:
- Backpropagation is effectively performed only over the remaining network
- The effective network is different for different inputs
- Gradients are obtained only for the weights and biases *from* “On” nodes *to* “On” nodes
  - For the remaining, the gradient is just 0

The pattern of dropped nodes changes for each input i.e. in every pass through the net
Statistical Interpretation

• For a network with a total of $N$ neurons, there are $2^N$ possible sub-networks
  – Obtained by choosing different subsets of nodes
  – Dropout *samples* over all $2^N$ possible networks
  – Effectively learns a network that *averages* over all possible networks
    • Bagging
The forward pass

- Input: $D$ dimensional vector $\mathbf{x} = [x_j, \ j = 1 \ldots D]$
- Set:
  - $D_0 = D$, is the width of the $0^{th}$ (input) layer
  - $y_j^{(0)} = x_j, \ j = 1 \ldots D; \ y_0^{(k=1\ldots N)} = x_0 = 1$
- For layer $k = 1 \ldots N$
  - For $j = 1 \ldots D_k$
    - $z_j^{(k)} = \sum_{i=0}^{N_k} w_{i,j}^{(k)} y_i^{(k-1)} + b_j^{(k)}$
    - $y_j^{(k)} = f_k(z_j^{(k)})$
    - If ($k = \text{dropout layer}$):
      - $\text{mask}(k,j) = \text{Bernoulli}(\alpha)$
      - If $\text{mask}(k,j) == 0$
        » $y_j^{(k)} = 0$
- Output:
  - $Y = y_j^{(N)}, j = 1 \ldots D_N$
Backward Pass

• Output layer (N):

\[ \frac{\partial \text{Div}}{\partial Y_i} = \frac{\partial \text{Div}(Y, d)}{\partial y_i^{(N)}} \]

\[ \frac{\partial \text{Div}}{\partial z_i^{(k)}} = f'_k \left( z_i^{(k)} \right) \frac{\partial \text{Div}}{\partial y_i^{(k)}} \]

• For layer \( k = N - 1 \) downto 0

  - For \( i = 1 \) ... \( D_k \)
    • If (not dropout layer OR \( \text{mask}(k, i) \))
      \[ \frac{\partial \text{Div}}{\partial y_i^{(k)}} = \sum_j w_{ij}^{(k+1)} \frac{\partial \text{Div}}{\partial z_j^{(k+1)}} \]
      \[ \frac{\partial \text{Div}}{\partial z_i^{(k)}} = f'_k \left( z_i^{(k)} \right) \frac{\partial \text{Div}}{\partial y_i^{(k)}} \]
      \[ \frac{\partial \text{Div}}{\partial w_{ij}^{(k+1)}} = y_j^{(k)} \frac{\partial \text{Div}}{\partial z_i^{(k+1)}} \text{ for } j = 1 \ldots D_{k+1} \]
    • Else
      \[ \frac{\partial \text{Div}}{\partial z_i^{(k)}} = 0 \]
What each neuron computes

- Each neuron actually has the following activation:

\[ y_i^{(k)} = D \sigma \left( \sum_j w_{ji}^{(k)} y_j^{(k-1)} + b_i^{(k)} \right) \]

  - Where \( D \) is a Bernoulli variable that takes a value 1 with probability \( \alpha \)

- \( D \) may be switched on or off for individual sub networks, but over the ensemble, the expected output of the neuron is

\[ y_i^{(k)} = \alpha \sigma \left( \sum_j w_{ji}^{(k)} y_j^{(k-1)} + b_i^{(k)} \right) \]

- During test time, we will use the expected output of the neuron
  - Which corresponds to the bagged average output
  - Consists of simply scaling the output of each neuron by \( \alpha \)
**Dropout during test: implementation**

- Instead of multiplying every output by $\alpha$, multiply all weights by $\alpha$.

- The equation for the output of the neuron is:
  $$y_i^{(k)} = \alpha \sigma(z_i^{(k)})$$

- Applying $\alpha$ to the output of the neuron and pushing it to all outgoing weights:
  $$z_i^{(k)} = \sum_j w_{ji}^{(k)} y_j^{(k-1)} + b_i^{(k)}$$

- The equation becomes:
  $$y_i^{(k)} = \alpha \sigma(z_i^{(k)}) = \sum_j w_{ji}^{(k)} \alpha \sigma(z_j^{(k-1)}) + b_i^{(k)} = \sum_j (\alpha w_{ji}^{(k)}) \sigma(z_j^{(k-1)}) + b_i^{(k)}$$

- The test weights are:
  $$W_{test} = \alpha W_{trained}$$
• Alternately, during *training*, replace the activation of all neurons in the network by \( \alpha^{-1}\sigma(.) \)
  
  – This does not affect the dropout procedure itself
  
  – We will use \( \sigma(.) \) as the activation during testing, and not modify the weights
The forward pass (training)

• Input: $D$ dimensional vector $\mathbf{x} = [x_j, j = 1 \ldots D]$

• Set:
  - $D_0 = D$, is the width of the 0th (input) layer
  - $y_j^{(0)} = x_j, j = 1 \ldots D$; $y_0^{(k=1\ldots N)} = x_0 = 1$

• For layer $k = 1 \ldots N$
  - For $j = 1 \ldots D_k$
    - $z_j^{(k)} = \sum_{i=0}^{N_k} w_{i,j}^{(k)} y_i^{(k-1)} + b_j^{(k)}$
    - $y_j^{(k)} = f_k(z_j^{(k)})$
    - If ($k = \text{dropout layer}$):
      - mask($k,j$) = Bernoulli($\alpha$)
      - If mask($k,j$)
        » $y_j^{(k)} = y_j^{(k)}/\alpha$
      - Else
        » $y_j^{(k)} = 0$

• Output:
  - $Y = y_j^{(N)}, j = 1 \ldots D_N$
Dropout: Typical results

- From Srivastava et al., 2013. Test error for different architectures on MNIST with and without dropout
  - 2-4 hidden layers with 1024-2048 units
Variations on dropout

- **Zoneout**: For RNNs
  - Randomly chosen units remain unchanged across a time transition

- **Dropconnect**
  - Drop individual connections, instead of nodes

- **Shakeout**
  - Scale *up* the weights of randomly selected weights
    - $|w| \rightarrow \alpha|w| + (1 - \alpha)c$
  - Fix remaining weights to a negative constant
    - $w \rightarrow -c$

- **Whiteout**
  - Add or multiply weight-dependent Gaussian noise to the signal on each connection
Other heuristics: Early stopping

• Continued training can result in severe overfitting to training data
  – Track performance on a held-out validation set
  – Apply one of several early-stopping criterion to terminate training when performance on validation set degrades significantly
Additional heuristics: Gradient clipping

- Often the derivative will be too high
  - When the divergence has a steep slope
  - This can result in instability
- **Gradient clipping**: set a ceiling on derivative value
  \[
  \text{if } \frac{\partial w}{\partial D} > \theta \text{ then } \frac{\partial w}{\partial D} = \theta
  \]
  - Typical \( \theta \) value is 5
Additional heuristics: Data Augmentation

- Available training data will often be small
- “Extend” it by distorting examples in a variety of ways to generate synthetic labelled examples
  - E.g. rotation, stretching, adding noise, other distortion
Other tricks

• Normalize the input:
  – Apply covariate shift to entire training data to make it 0 mean, unit variance
  – Equivalent of batch norm on input

• A variety of other tricks are applied
  – Initialization techniques
    • Typically initialized randomly
    • Key point: neurons with identical connections that are identically initialized will never diverge
  – Practice makes man perfect
Setting up a problem

- Obtain training data
  - Use appropriate representation for inputs and outputs
- Choose network architecture
  - More neurons need more data
  - Deep is better, but harder to train
- Choose the appropriate divergence function
  - Choose regularization
- Choose heuristics (batch norm, dropout, etc.)
- Choose optimization algorithm
  - E.g. Adagrad
- Perform a grid search for hyper parameters (learning rate, regularization parameter, ...) on held-out data
- Train
  - Evaluate periodically on validation data, for early stopping if required
In closing

• Have outlined the process of training neural networks
  – Some history
  – A variety of algorithms
  – Gradient-descent based techniques
  – Regularization for generalization
  – Algorithms for convergence
  – Heuristics

• Practice makes perfect..