Optimization
(Gradient Descent & Backprop)

Thanks to Max Morrison for a number of slides
Supervised Machine Learning in one slide

1. Pick data $X$, labels $Y$, model $M(\theta)$ and loss function $L(X, Y; \theta)$

2. Initialize model parameters $\theta$, somehow

3. Measure model performance with the loss function $L(X, Y; \theta)$

HOW?

4. Modify parameters $\theta$ somehow, hoping to improve $L(X, Y; \theta)$

5. Repeat 3 and 4 until you stop improving or run out of time
A common approach to picking the next parameters

**HOW?**

1. Measure how the loss changes when we change the parameters \( \theta \) slightly

2. Pick the next set of parameters to be close to the current set, but in the direction that most changes the loss function for the better

3. Repeat
Slope vs gradient

- Slope of $f(\theta)$ is a scalar describing a line perpendicular to the tangent of the function at that point.

- Gradient $\nabla f(\theta)$ is a vector describing a hyperplane perpendicular to the tangent at $\theta$. 
What does the gradient tell us?

• If the loss function and hypothesis function encoded by the model are differentiable* (i.e., the gradient exists)

• We can evaluate the gradient for some fixed value of $\theta$ and get the direction in which the loss increases fastest

*or subdifferentiable
What does the gradient tell us?

- We want to *decrease* our loss, so let’s go the other way instead.
Gradient Descent: Promises & Caveats

• Much faster than guessing new parameters randomly
• Finds the global optimum only if the objective function is convex

\[
\text{Loss } L(X, Y; \theta)
\]

\( \theta \) : the value of some parameter
Step Size: how far should we go?

- The gradient we calculated was based on a fixed value of $\theta$
- As we move away from this point, the gradient changes

If the step size is too large, we may overshoot the minimum

If the step size is too small, we need to take more steps (more computation)
Gradient Descent Pseudocode

Initialize $\theta^{(0)}$

Repeat until stopping condition met:

$$\theta^{(t+1)} = \theta_t - \eta \nabla L(X, Y; \theta^{(t)})$$

Return $\theta^{(t_{max})}$

$\theta^{(t)}$ are the parameters of the model at time step $t$

$\nabla L(X, Y; \theta^{(t)})$ is the gradient of the loss function with respect to model parameters $\theta^{(t)}$

$\eta$ controls the step size

$\theta^{(t_{max})}$ is the set of parameters that did best on the loss function.
Design choices

Initialize $\theta^{(0)}$

Repeat until stopping condition met:

$$
\theta^{(t+1)} = \theta_t - \eta \nabla L(X, Y, \theta^{(t)})
$$

Return $\theta^{(t_{max})}$

- Initialization of $\theta$
- Convergence criterion
- Choosing a loss function
- How much data to use at each step (batch size)
- Step size for updating model parameters
Parameter Initialization

Common initializations:
- $\theta^{(0)} = 0$
- $\theta^{(0)} = \text{random values}$

What happens if our initialization is bad?
- Convergence to a local minimum
- No way to determine if you’ve converged to the global minimum
Knowing when to stop gradient descent

• Stop when the gradient is close (within $\varepsilon$) to 0 (i.e., we reached a minimum)

• Stop after some fixed number of iterations

• Stop when the loss on a validation set stops decreasing
  • This helps prevent overfitting
Stochastic, Batch, Mini-Batch Descent

• Call $D$ the set $X,Y$ pairs we measure loss on

• In **batch gradient descent**, the loss is a function of both the parameters $\theta$ and the set of all training data $D$. (What if if $|D| > \text{memory?}$)

• In **stochastic gradient descent**, loss is a function of the parameters and a different single random training sample at each iteration.

• In **mini-batch gradient descent**, random subsets of the data (e.g. 100 examples) are used at each step in the iteration.
Different data, different loss

- Call $D$ the set $X,Y$ pairs we measure loss on.
- If $D$ changes, then the landscape of the loss function changes.
- You typically won’t know how it has changed.

$\theta$: the value of some parameter
Loss functions
A good objective (loss) function $L(X, Y; \theta)$

1. $L(X, Y; \theta) \geq 0$
2. $L(X, Y; \theta)$ decreases as performance improves
3. $L(X, Y; \theta)$ is differentiable*, with respect to $\theta$
4. The gradient of $L$ is bounded ... $0 < |\nabla L| \ll \infty$

*or subdifferentiable

Required
- data
- labels
- parameters

Required for gradient descent
- helpful

For gradient descent

*or subdifferentiable
Example: 01 loss

\[ g(x) = w_0 + w_1x_1 + w_2x_2 = 0 \]

\[ h(x) = \begin{cases} 
1 & \text{if } g(x) > 0 \\
-1 & \text{otherwise}
\end{cases} \]

\[ SSE = \sum_{i=1}^{n} (y_i - h(x_i))^2 \]

SSE is same everywhere in the blue
Gradient 0 in the blue region!
The 0 1 Loss function

• A generic term for machine learning model parameters is $\theta$

• Loss = 1 if $y \neq h_\theta(x)$, else it’s 0

• A count of mislabeled items

• Results in a step function

• Not useful for gradient descent
Perceptron Problem: The step function

\[ h(x) = \begin{cases} 
1 & \text{if } 0 < \mathbf{w}^T \mathbf{x} \\
-1 & \text{else} 
\end{cases} \]
Solution: Remove the step function

\[ h(x) = w^T x \]
Squared loss: we now have a gradient

- Our hypothesis function is now $h_\theta(\mathbf{x})$ where $\theta$ are the model parameters.

- We write our loss function as:
  \[
  L_s(X, Y; \theta) = \frac{1}{2N} \sum_{i=1}^{N} (y_i - h_\theta(x_i))^2
  \]

- If we use a linear model, then:
  \[
  h_\theta(\mathbf{x}) = \theta^T \mathbf{x}
  \]
A simple example: where do you draw the line?

Happy faces have label $y = +1$ and sad faces have label $y = -1$.

We have a linear model with 2 parameters: $\hat{y} = \mathbf{w}^T \mathbf{x} = w_0 x_0 + w_1 x_1$

Our loss function will be sum-of-squared-errors:

$$L(X, Y, \mathbf{w}) = \frac{1}{2N} \sum_{i=1}^{N} (y_i - \hat{y}_i)^2$$

How does the loss change as we move the line defined by $w_0$? Can we use that to decide where to move it? What does $w_1$ do?
Measuring loss for a linear unit

• Model’s hypothesis $h_\theta(x)$ function outputs a label estimate $\hat{y}$, given its parameters $\theta$. Let’s call them the weights, $w$

$$\hat{y} = h_\theta(x) = w^T x$$

• Sum of squared errors loss function:

$$L(X, Y, w) = \frac{1}{2N} \sum_{i=1}^{N} (y_i - \hat{y}_i)^2$$

This $\frac{1}{2}$ makes the derivative simpler

$N$ is a normalizing factor so different batch sizes have comparable loss. Safe to remove.

$i$ is the index to the $i$th example $x_i$ and its label $y_i$. $y_i$ is the true label for example $i$.
If we consider a single example, then...

\[ L(X, Y, \mathbf{w}) = \frac{1}{2N} \sum_{i=1}^{N} (y_i - \hat{y}_i)^2 \]

Setting the number of data points \( N = 1 \) results in...

\[ L(X, Y, \mathbf{w}) = \frac{1}{2} (y - \hat{y})^2 \]
For each dimension $i$, take the partial derivative

$$\frac{\partial L}{\partial w_i} = \frac{\partial L}{\partial \hat{y}} \frac{\partial \hat{y}}{\partial w_i}$$

gives the change of our loss function $L$ with respect to weight $w_i$

For a linear unit: $\hat{y} = w^T x$ and loss function: $L = \frac{1}{2} (y - \hat{y})^2$, then...

$$\frac{\partial L}{\partial \hat{y}} = (y - \hat{y}) = (y - w^T x)$$

Let’s calculate $\frac{\partial \hat{y}}{\partial w_i}$. Recall $\hat{y} = w^T x = w_0 x_0 \ldots + w_i x_i \ldots + w_d x_d$

$w_i$ is the only variable weight in this partial derivative, therefore:

$$\frac{\partial \hat{y}}{\partial w_i} = x_i$$

Therefore, $\frac{\partial L}{\partial w_i} = (y - w^T x) x_i$
We now have each weight’s portion of the gradient for a linear model.

\[
\frac{\partial L}{\partial w_i} = x_i(y - w^T x)
\]

\[
\nabla L(X, Y; \theta^{(t)}) = \left[ \frac{\partial L}{\partial w_0}, \ldots, \frac{\partial L}{\partial w_i}, \ldots, \frac{\partial L}{\partial w_d} \right]
\]
The gradient can now be used here

**Initialize** \(\theta^{(0)}\)

Repeat until stopping condition met:

\[
\theta^{(t+1)} = \theta_t - \eta \nabla L(X, Y; \theta^{(t)})
\]

**Return** \(\theta^{(t_{\text{max}})}\)

\(\theta^{(t)}\) are the parameters of the model at time step \(t\)

\(\nabla L(X, Y; \theta^{(t)})\) is the gradient of the loss function with respect to model parameters \(\theta^{(t)}\)

\(\eta\) controls the step size

\(\theta^{(t_{\text{max}})}\) is the set of parameters that did best on the loss function.
Sigmoid (aka Logistic) function: best of both

- Perceptron
  
  \[ f(x) = \begin{cases} 1 & \text{if } 0 < \sum_{i=0}^{n} w_i x_i \\ -1 & \text{else} \end{cases} \]

- Linear
  
  \[ f(x) = \mathbf{w}^T \mathbf{x} = \sum_{i=0}^{n} w_i x_i \]

- Sigmoid
  
  \[ f(x) = \sigma(x) = \frac{1}{1 + e^{-(\mathbf{w}^T \mathbf{x})}} \]
What’s cool about the sigmoid function

• It looks like a rounded step function, so we can build circuits of arbitrary functions like we can with perceptrons

• It has non-zero slope everywhere and no sharp corners

• The derivative of the function is this: \( \frac{d\sigma(z)}{dz} = \sigma(z)(1 - \sigma(z)) \)

• ...and it’s easy to plug into the gradient descent algorithm to get the learning rule.
For each dimension $i$, take the partial derivative

$$\frac{\partial L}{\partial w_i} = \frac{\partial L}{\partial \hat{y}} \frac{\partial \hat{y}}{\partial z} \frac{\partial z}{\partial w_i}$$

gives the change of our loss function $L$ with respect to weight $w_i$

Here, $L = \frac{1}{2} (y - \hat{y})^2$ and $\hat{y} = \sigma(z) = \frac{1}{1 + e^{-z}}$ and $z = w^T x$

Therefore $\frac{\partial L}{\partial \hat{y}} = (y - \hat{y}) = (y - \sigma(z))$

..and $\frac{\partial \hat{y}}{\partial z} = \sigma(z)(1 - \sigma(z))$, as was given to us.

...and $\frac{\partial z}{\partial w_i} = x_i$, since $z = w^T x = w_0 x_0 \ldots + w_i x_i \ldots + w_d x_d$

Therefore, $\frac{\partial L}{\partial w_i} = (y - \sigma(z))\sigma(z)(1 - \sigma(z))x_i$
For each dimension $i$, take the partial derivative

From the previous slide: \[
\frac{\partial L}{\partial w_i} = (y - \sigma(z))\sigma(z)(1 - \sigma(z))x_i
\]

Let’s compose $\sigma(z) = \frac{1}{1+e^{-z}}$ and $z = w^T x$ into one function (called $\sigma(x)$), to get the following:

$\sigma(x) = \frac{1}{1+e^{-w^T x}}$

This lets us now write the change in loss as:

\[
\frac{\partial L}{\partial w_i} = (y - \sigma(x))\sigma(x)(1 - \sigma(x))x_i
\]
Backpropagation of error
Where we left off

• We have the $\sigma(x)$ sigmoid function that we can train with gradient descent, because it’s differentiable and has a non-zero gradient everywhere.

• We can plug multiple sigmoids together to form arbitrary Boolean functions, by just interpreting the last output with $\text{sign}(\sigma(x))$.

• We now need a way to have error from the output sigmoid function to flow to the input, so we can adjust the parameters of every $\sigma(x)$ on the path from the input to the output when we do our gradient descent.
Consider one output node

Let’s define a function…

\[ \delta = (y - \sigma(x)) \sigma(x)(1 - \sigma(x)) \]

Now this…

\[ \frac{\partial L}{\partial w_i} = (y - \sigma(x))\sigma(x)(1 - \sigma(x))x_i \]

…becomes this: \[ \frac{\partial L}{\partial w_i} = \delta x_i \]

For any output node \( k \) we just use this, as before.
Consider one hidden node

For a hidden node $h$ we need to redefine $\delta$. Instead of comparing the output of the node to a known target output $y$, we look at its contribution to the output of the $k$ nodes it is connected to at the next layer.

\[ \delta = \left( \sum_k w_k \delta_k \right) \sigma(x)(1 - \sigma(x)) \]

…and we then do: \[
\frac{\partial L}{\partial w_i} = \delta x_i
\]

We can do this repeatedly for multiple hidden layers.