

CS229 Lecture notes

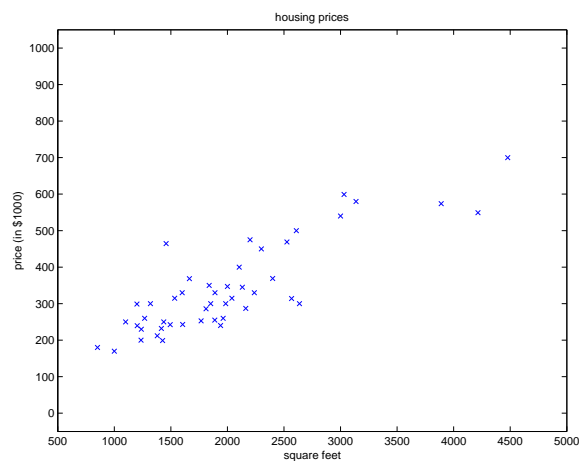
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Supervised learning

Let's start by talking about a few examples of supervised learning problems. Suppose we have a dataset giving the living areas and prices of 47 houses from Portland, Oregon:

Living area (feet ²)	Price (1000\$)
2104	400
1600	330
2400	369
1416	232
3000	540
⋮	⋮

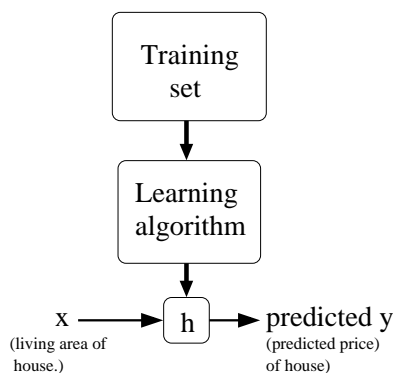
We can plot this data:



Given data like this, how can we learn to predict the prices of other houses in Portland, as a function of the size of their living areas?

To establish notation for future use, we'll use $x^{(i)}$ to denote the “input” variables (living area in this example), also called input **features**, and $y^{(i)}$ to denote the “output” or **target** variable that we are trying to predict (price). A pair $(x^{(i)}, y^{(i)})$ is called a **training example**, and the dataset that we'll be using to learn—a list of m training examples $\{(x^{(i)}, y^{(i)}); i = 1, \dots, m\}$ —is called a **training set**. Note that the superscript “ (i) ” in the notation is simply an index into the training set, and has nothing to do with exponentiation. We will also use \mathcal{X} denote the space of input values, and \mathcal{Y} the space of output values. In this example, $\mathcal{X} = \mathcal{Y} = \mathbb{R}$.

To describe the supervised learning problem slightly more formally, our goal is, given a training set, to learn a function $h : \mathcal{X} \mapsto \mathcal{Y}$ so that $h(x)$ is a “good” predictor for the corresponding value of y . For historical reasons, this function h is called a **hypothesis**. Seen pictorially, the process is therefore like this:



When the target variable that we're trying to predict is continuous, such as in our housing example, we call the learning problem a **regression** problem. When y can take on only a small number of discrete values (such as if, given the living area, we wanted to predict if a dwelling is a house or an apartment, say), we call it a **classification** problem.

Part I

Linear Regression

To make our housing example more interesting, let's consider a slightly richer dataset in which we also know the number of bedrooms in each house:

Living area (feet ²)	#bedrooms	Price (1000\$)
2104	3	400
1600	3	330
2400	3	369
1416	2	232
3000	4	540
⋮	⋮	⋮

Here, the x 's are two-dimensional vectors in \mathbb{R}^2 . For instance, $x_1^{(i)}$ is the living area of the i -th house in the training set, and $x_2^{(i)}$ is its number of bedrooms. (In general, when designing a learning problem, it will be up to you to decide what features to choose, so if you are out in Portland gathering housing data, you might also decide to include other features such as whether each house has a fireplace, the number of bathrooms, and so on. We'll say more about feature selection later, but for now let's take the features as given.)

To perform supervised learning, we must decide how we're going to represent functions/hypotheses h in a computer. As an initial choice, let's say we decide to approximate y as a linear function of x :

$$h_\theta(x) = \theta_0 + \theta_1 x_1 + \theta_2 x_2$$

Here, the θ_i 's are the **parameters** (also called **weights**) parameterizing the space of linear functions mapping from \mathcal{X} to \mathcal{Y} . When there is no risk of confusion, we will drop the θ subscript in $h_\theta(x)$, and write it more simply as $h(x)$. To simplify our notation, we also introduce the convention of letting $x_0 = 1$ (this is the **intercept term**), so that

$$h(x) = \sum_{i=0}^n \theta_i x_i = \theta^T x,$$

where on the right-hand side above we are viewing θ and x both as vectors, and here n is the number of input variables (not counting x_0).

Now, given a training set, how do we pick, or learn, the parameters θ ? One reasonable method seems to be to make $h(x)$ close to y , at least for the training examples we have. To formalize this, we will define a function that measures, for each value of the θ 's, how close the $h(x^{(i)})$'s are to the corresponding $y^{(i)}$'s. We define the **cost function**:

$$J(\theta) = \frac{1}{2} \sum_{i=1}^m (h_{\theta}(x^{(i)}) - y^{(i)})^2.$$

If you've seen linear regression before, you may recognize this as the familiar least-squares cost function that gives rise to the **ordinary least squares** regression model. Whether or not you have seen it previously, let's keep going, and we'll eventually show this to be a special case of a much broader family of algorithms.

1 LMS algorithm

We want to choose θ so as to minimize $J(\theta)$. To do so, let's use a search algorithm that starts with some "initial guess" for θ , and that repeatedly changes θ to make $J(\theta)$ smaller, until hopefully we converge to a value of θ that minimizes $J(\theta)$. Specifically, let's consider the **gradient descent** algorithm, which starts with some initial θ , and repeatedly performs the update:

$$\theta_j := \theta_j - \alpha \frac{\partial}{\partial \theta_j} J(\theta).$$

(This update is simultaneously performed for all values of $j = 0, \dots, n$.) Here, α is called the **learning rate**. This is a very natural algorithm that repeatedly takes a step in the direction of steepest decrease of J .

In order to implement this algorithm, we have to work out what is the partial derivative term on the right hand side. Let's first work it out for the case of if we have only one training example (x, y) , so that we can neglect the sum in the definition of J . We have:

$$\begin{aligned} \frac{\partial}{\partial \theta_j} J(\theta) &= \frac{\partial}{\partial \theta_j} \frac{1}{2} (h_{\theta}(x) - y)^2 \\ &= 2 \cdot \frac{1}{2} (h_{\theta}(x) - y) \cdot \frac{\partial}{\partial \theta_j} (h_{\theta}(x) - y) \\ &= (h_{\theta}(x) - y) \cdot \frac{\partial}{\partial \theta_j} \left(\sum_{i=0}^n \theta_i x_i - y \right) \\ &= (h_{\theta}(x) - y) x_j \end{aligned}$$

For a single training example, this gives the update rule:¹

$$\theta_j := \theta_j + \alpha (y^{(i)} - h_\theta(x^{(i)})) x_j^{(i)}.$$

The rule is called the **LMS** update rule (LMS stands for “least mean squares”), and is also known as the **Widrow-Hoff** learning rule. This rule has several properties that seem natural and intuitive. For instance, the magnitude of the update is proportional to the **error** term $(y^{(i)} - h_\theta(x^{(i)}))$; thus, for instance, if we are encountering a training example on which our prediction nearly matches the actual value of $y^{(i)}$, then we find that there is little need to change the parameters; in contrast, a larger change to the parameters will be made if our prediction $h_\theta(x^{(i)})$ has a large error (i.e., if it is very far from $y^{(i)}$).

We’d derived the LMS rule for when there was only a single training example. There are two ways to modify this method for a training set of more than one example. The first is replace it with the following algorithm:

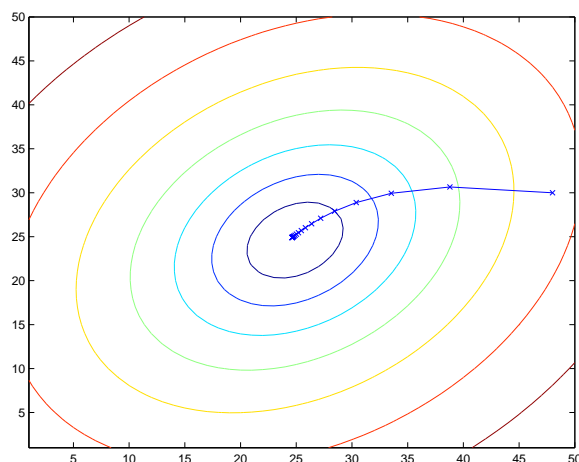
Repeat until convergence {

$$\theta_j := \theta_j + \alpha \sum_{i=1}^m (y^{(i)} - h_\theta(x^{(i)})) x_j^{(i)} \quad (\text{for every } j).$$

}

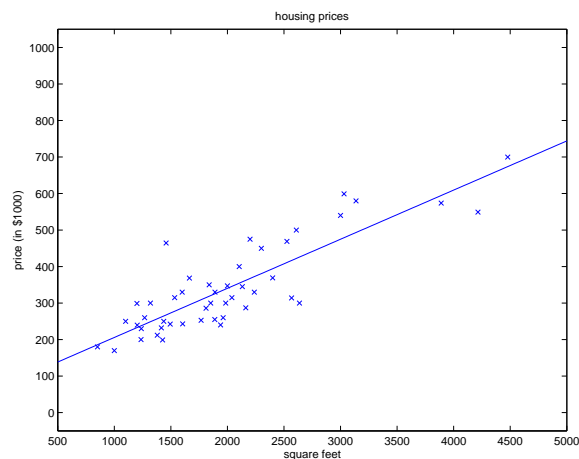
The reader can easily verify that the quantity in the summation in the update rule above is just $\partial J(\theta)/\partial \theta_j$ (for the original definition of J). So, this is simply gradient descent on the original cost function J . This method looks at every example in the entire training set on every step, and is called **batch gradient descent**. Note that, while gradient descent can be susceptible to local minima in general, the optimization problem we have posed here for linear regression has only one global, and no other local, optima; thus gradient descent always converges (assuming the learning rate α is not too large) to the global minimum. Indeed, J is a convex quadratic function. Here is an example of gradient descent as it is run to minimize a quadratic function.

¹We use the notation “ $a := b$ ” to denote an operation (in a computer program) in which we *set* the value of a variable a to be equal to the value of b . In other words, this operation overwrites a with the value of b . In contrast, we will write “ $a = b$ ” when we are asserting a statement of fact, that the value of a is equal to the value of b .



The ellipses shown above are the contours of a quadratic function. Also shown is the trajectory taken by gradient descent, which was initialized at $(48, 30)$. The x 's in the figure (joined by straight lines) mark the successive values of θ that gradient descent went through.

When we run batch gradient descent to fit θ on our previous dataset, to learn to predict housing price as a function of living area, we obtain $\theta_0 = 71.27$, $\theta_1 = 0.1345$. If we plot $h_\theta(x)$ as a function of x (area), along with the training data, we obtain the following figure:



If the number of bedrooms were included as one of the input features as well, we get $\theta_0 = 89.60$, $\theta_1 = 0.1392$, $\theta_2 = -8.738$.

The above results were obtained with batch gradient descent. There is an alternative to batch gradient descent that also works very well. Consider the following algorithm:

```

Loop {
    for i=1 to m, {
         $\theta_j := \theta_j + \alpha (y^{(i)} - h_{\theta}(x^{(i)})) x_j^{(i)}$     (for every  $j$ ).
    }
}

```

In this algorithm, we repeatedly run through the training set, and each time we encounter a training example, we update the parameters according to the gradient of the error with respect to that single training example only. This algorithm is called **stochastic gradient descent** (also **incremental gradient descent**). Whereas batch gradient descent has to scan through the entire training set before taking a single step—a costly operation if m is large—stochastic gradient descent can start making progress right away, and continues to make progress with each example it looks at. Often, stochastic gradient descent gets θ “close” to the minimum much faster than batch gradient descent. (Note however that it may never “converge” to the minimum, and the parameters θ will keep oscillating around the minimum of $J(\theta)$; but in practice most of the values near the minimum will be reasonably good approximations to the true minimum.²) For these reasons, particularly when the training set is large, stochastic gradient descent is often preferred over batch gradient descent.

2 The normal equations

Gradient descent gives one way of minimizing J . Let’s discuss a second way of doing so, this time performing the minimization explicitly and without resorting to an iterative algorithm. In this method, we will minimize J by explicitly taking its derivatives with respect to the θ_j ’s, and setting them to zero. To enable us to do this without having to write reams of algebra and pages full of matrices of derivatives, let’s introduce some notation for doing calculus with matrices.

²While it is more common to run stochastic gradient descent as we have described it and with a fixed learning rate α , by slowly letting the learning rate α decrease to zero as the algorithm runs, it is also possible to ensure that the parameters will converge to the global minimum rather than merely oscillate around the minimum.

2.1 Matrix derivatives

For a function $f : \mathbb{R}^{m \times n} \mapsto \mathbb{R}$ mapping from m -by- n matrices to the real numbers, we define the derivative of f with respect to A to be:

$$\nabla_A f(A) = \begin{bmatrix} \frac{\partial f}{\partial A_{11}} & \cdots & \frac{\partial f}{\partial A_{1n}} \\ \vdots & \ddots & \vdots \\ \frac{\partial f}{\partial A_{m1}} & \cdots & \frac{\partial f}{\partial A_{mn}} \end{bmatrix}$$

Thus, the gradient $\nabla_A f(A)$ is itself an m -by- n matrix, whose (i, j) -element is $\partial f / \partial A_{ij}$. For example, suppose $A = \begin{bmatrix} A_{11} & A_{12} \\ A_{21} & A_{22} \end{bmatrix}$ is a 2-by-2 matrix, and the function $f : \mathbb{R}^{2 \times 2} \mapsto \mathbb{R}$ is given by

$$f(A) = \frac{3}{2}A_{11} + 5A_{12}^2 + A_{21}A_{22}.$$

Here, A_{ij} denotes the (i, j) entry of the matrix A . We then have

$$\nabla_A f(A) = \begin{bmatrix} \frac{3}{2} & 10A_{12} \\ A_{22} & A_{21} \end{bmatrix}.$$

We also introduce the **trace** operator, written “tr.” For an n -by- n (square) matrix A , the trace of A is defined to be the sum of its diagonal entries:

$$\text{tr} A = \sum_{i=1}^n A_{ii}$$

If a is a real number (i.e., a 1-by-1 matrix), then $\text{tr} a = a$. (If you haven’t seen this “operator notation” before, you should think of the trace of A as $\text{tr}(A)$, or as application of the “trace” function to the matrix A . It’s more commonly written without the parentheses, however.)

The trace operator has the property that for two matrices A and B such that AB is square, we have that $\text{tr} AB = \text{tr} BA$. (Check this yourself!) As corollaries of this, we also have, e.g.,

$$\begin{aligned} \text{tr} ABC &= \text{tr} CAB = \text{tr} BCA, \\ \text{tr} ABCD &= \text{tr} DABC = \text{tr} CDAB = \text{tr} BCDA. \end{aligned}$$

The following properties of the trace operator are also easily verified. Here, A and B are square matrices, and a is a real number:

$$\begin{aligned} \text{tr} A &= \text{tr} A^T \\ \text{tr}(A + B) &= \text{tr} A + \text{tr} B \\ \text{tr} aA &= a \text{tr} A \end{aligned}$$

We now state without proof some facts of matrix derivatives (we won't need some of these until later this quarter). Equation (4) applies only to non-singular square matrices A , where $|A|$ denotes the determinant of A . We have:

$$\nabla_A \text{tr} AB = B^T \tag{1}$$

$$\nabla_{A^T} f(A) = (\nabla_A f(A))^T \tag{2}$$

$$\nabla_A \text{tr} ABA^T C = CAB + C^T AB^T \tag{3}$$

$$\nabla_A |A| = |A|(A^{-1})^T. \tag{4}$$

To make our matrix notation more concrete, let us now explain in detail the meaning of the first of these equations. Suppose we have some fixed matrix $B \in \mathbb{R}^{n \times m}$. We can then define a function $f : \mathbb{R}^{m \times n} \mapsto \mathbb{R}$ according to $f(A) = \text{tr} AB$. Note that this definition makes sense, because if $A \in \mathbb{R}^{m \times n}$, then AB is a square matrix, and we can apply the trace operator to it; thus, f does indeed map from $\mathbb{R}^{m \times n}$ to \mathbb{R} . We can then apply our definition of matrix derivatives to find $\nabla_A f(A)$, which will itself be an m -by- n matrix. Equation (1) above states that the (i, j) entry of this matrix will be given by the (i, j) -entry of B^T , or equivalently, by B_{ji} .

The proofs of Equations (1-3) are reasonably simple, and are left as an exercise to the reader. Equations (4) can be derived using the adjoint representation of the inverse of a matrix.³

2.2 Least squares revisited

Armed with the tools of matrix derivatives, let us now proceed to find in closed-form the value of θ that minimizes $J(\theta)$. We begin by re-writing J in matrix-vectorial notation.

Given a training set, define the **design matrix** X to be the m -by- n matrix (actually m -by- $n + 1$, if we include the intercept term) that contains

³If we define A' to be the matrix whose (i, j) element is $(-1)^{i+j}$ times the determinant of the square matrix resulting from deleting row i and column j from A , then it can be proved that $A^{-1} = (A')^T / |A|$. (You can check that this is consistent with the standard way of finding A^{-1} when A is a 2-by-2 matrix. If you want to see a proof of this more general result, see an intermediate or advanced linear algebra text, such as Charles Curtis, 1991, *Linear Algebra*, Springer.) This shows that $A' = |A|(A^{-1})^T$. Also, the determinant of a matrix can be written $|A| = \sum_j A_{ij} A'_{ij}$. Since $(A')_{ij}$ does not depend on A_{ij} (as can be seen from its definition), this implies that $(\partial / \partial A_{ij})|A| = A'_{ij}$. Putting all this together shows the result.

the training examples' input values in its rows:

$$X = \begin{bmatrix} - (x^{(1)})^T - \\ - (x^{(2)})^T - \\ \vdots \\ - (x^{(m)})^T - \end{bmatrix}.$$

Also, let \vec{y} be the m -dimensional vector containing all the target values from the training set:

$$\vec{y} = \begin{bmatrix} y^{(1)} \\ y^{(2)} \\ \vdots \\ y^{(m)} \end{bmatrix}.$$

Now, since $h_{\theta}(x^{(i)}) = (x^{(i)})^T \theta$, we can easily verify that

$$\begin{aligned} X\theta - \vec{y} &= \begin{bmatrix} (x^{(1)})^T \theta \\ \vdots \\ (x^{(m)})^T \theta \end{bmatrix} - \begin{bmatrix} y^{(1)} \\ \vdots \\ y^{(m)} \end{bmatrix} \\ &= \begin{bmatrix} h_{\theta}(x^{(1)}) - y^{(1)} \\ \vdots \\ h_{\theta}(x^{(m)}) - y^{(m)} \end{bmatrix}. \end{aligned}$$

Thus, using the fact that for a vector z , we have that $z^T z = \sum_i z_i^2$:

$$\begin{aligned} \frac{1}{2}(X\theta - \vec{y})^T (X\theta - \vec{y}) &= \frac{1}{2} \sum_{i=1}^m (h_{\theta}(x^{(i)}) - y^{(i)})^2 \\ &= J(\theta) \end{aligned}$$

Finally, to minimize J , let's find its derivatives with respect to θ . Combining Equations (2) and (3), we find that

$$\nabla_{A^T} \text{tr} A B A^T C = B^T A^T C^T + B A^T C \quad (5)$$

Hence,

$$\begin{aligned}
\nabla_{\theta} J(\theta) &= \nabla_{\theta} \frac{1}{2} (X\theta - \vec{y})^T (X\theta - \vec{y}) \\
&= \frac{1}{2} \nabla_{\theta} (\theta^T X^T X \theta - \theta^T X^T \vec{y} - \vec{y}^T X \theta + \vec{y}^T \vec{y}) \\
&= \frac{1}{2} \nabla_{\theta} \text{tr} (\theta^T X^T X \theta - \theta^T X^T \vec{y} - \vec{y}^T X \theta + \vec{y}^T \vec{y}) \\
&= \frac{1}{2} \nabla_{\theta} (\text{tr} \theta^T X^T X \theta - 2 \text{tr} \vec{y}^T X \theta) \\
&= \frac{1}{2} (X^T X \theta + X^T X \theta - 2 X^T \vec{y}) \\
&= X^T X \theta - X^T \vec{y}
\end{aligned}$$

In the third step, we used the fact that the trace of a real number is just the real number; the fourth step used the fact that $\text{tr} A = \text{tr} A^T$, and the fifth step used Equation (5) with $A^T = \theta$, $B = B^T = X^T X$, and $C = I$, and Equation (1). To minimize J , we set its derivatives to zero, and obtain the **normal equations**:

$$X^T X \theta = X^T \vec{y}$$

Thus, the value of θ that minimizes $J(\theta)$ is given in closed form by the equation

$$\theta = (X^T X)^{-1} X^T \vec{y}.$$