exploreCSR CoreML Workshop

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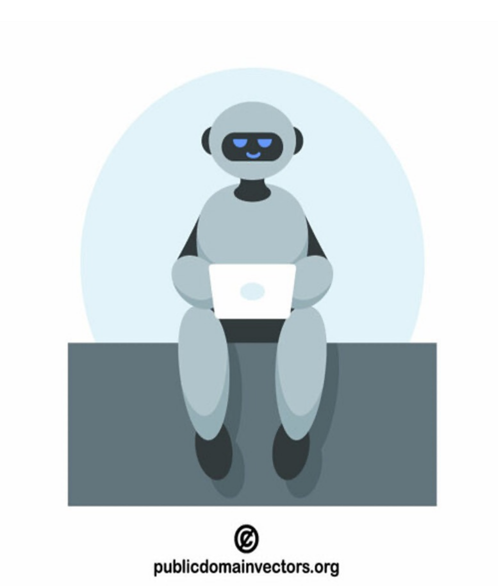
What is Machine Learning?



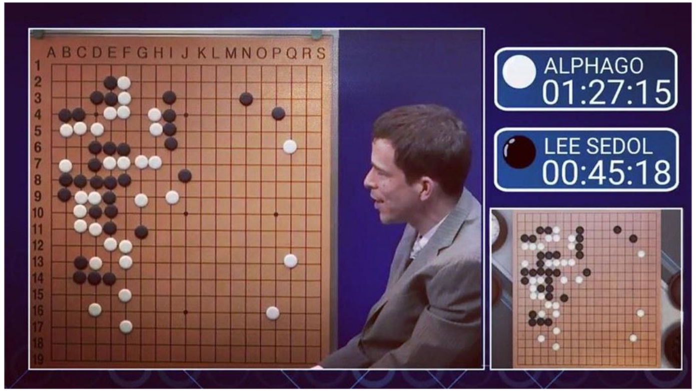
"Humans appear to be able to learn new concepts without needing to be programmed explicitly in any conventional sense. In this paper we regard learning as the phenomenon of knowledge acquisition in the absence of explicit programming."

--- A Theory of the Learnable, 1984, Leslie Valiant

"A computer program is said to learn from experience E with respect to some class of tasks T and performance measure P, if its performance at tasks in T, as measured by P, improves with experience E."

--- Machine Learning, 1998, Tom Mitchell

AlphaGo

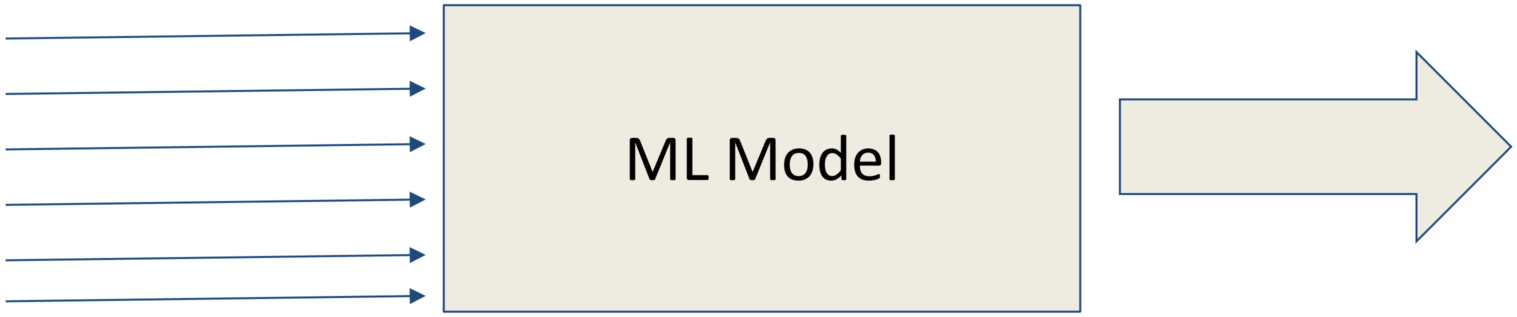


what is chatgpt

I am ChatGPT, a large language model created by OpenAI, designed to answer questions and generate human-like text based on a vast dataset of written content. I use deep learning algorithms to analyze and understand the context of the questions asked, and then generate a response that is relevant and helpful.

Today's Workshop:

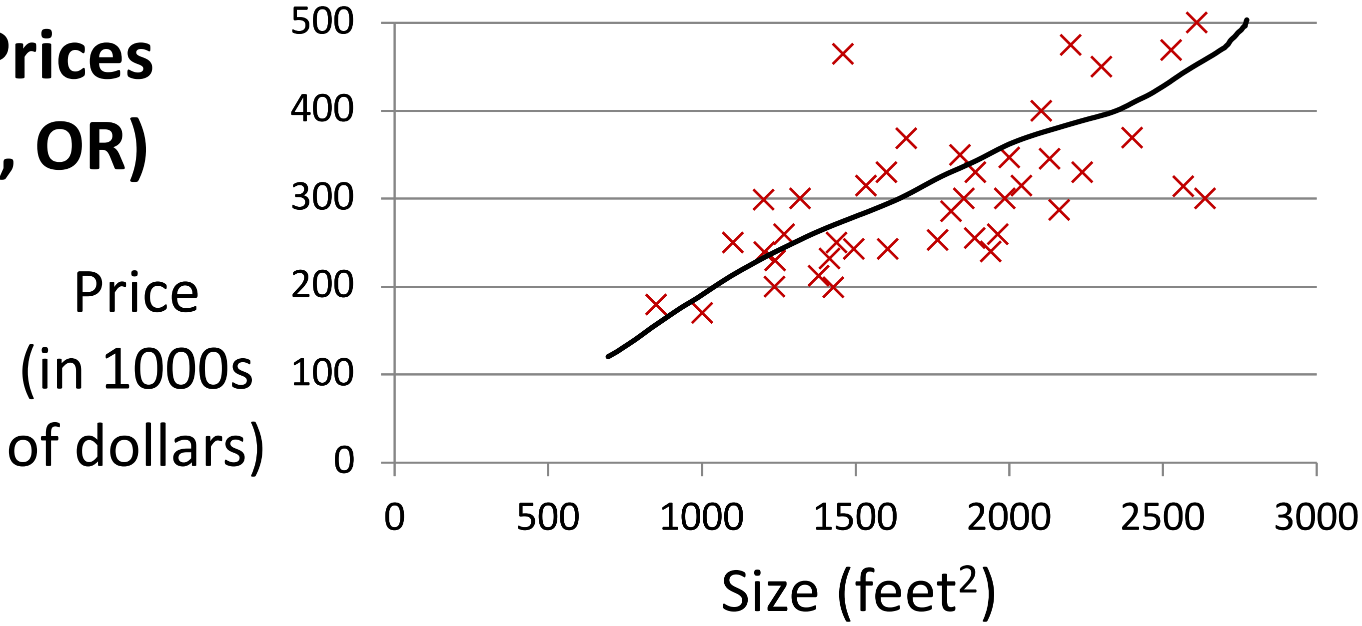
1. Understand the fundamentals of ML models
2. Understand how to train a ML model



Data flow in

We use the slides from Professor Andrew Ng in Stanford University

Housing Prices (Portland, OR)



Supervised Learning

Given the “right answer” for each example in the data.

Regression Problem

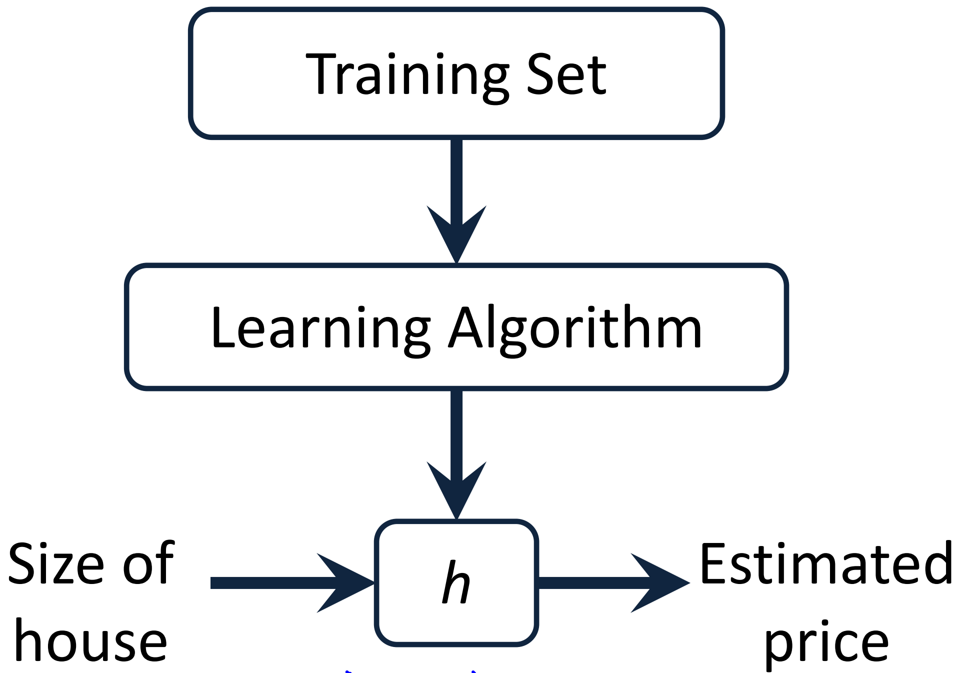
Predict real-valued output

Training set of housing prices (Portland, OR)

Size in feet^2 (x)	**Price ($) in 1000's (y)**
2104	460
1416	232
1534	315
852	178
…	…

Notation:

m = Number of training examples
x’s = “input” variable / features
y’s = “output” variable / “target” variable



x

hypothesis

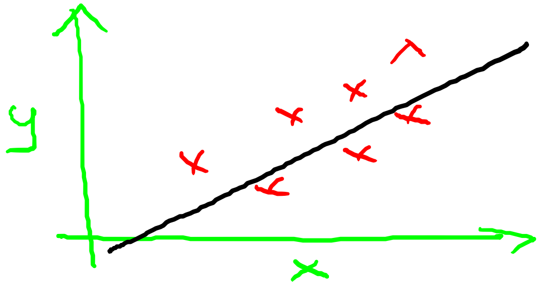
(estimated value of y)

h maps from x's to y's.

How do we represent *h* ?

$h_\theta(x) = \theta_0 + \theta_1 x$

Shorthand: $h(x)$



$h(x) = \theta_0 + \theta_1 x$

Linear regression with one variable. (x)

Univariate linear regression.

one variable

Training Set

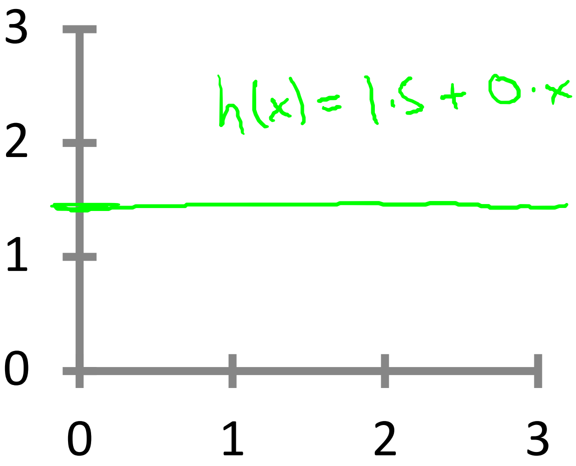
Size in feet^2 (x)	Price ($) in 1000's (y)
2104	460
1416	232
1534	315
852	178
…	…

Hypothesis: $h_\theta(x) = \theta_0 + \theta_1 x$

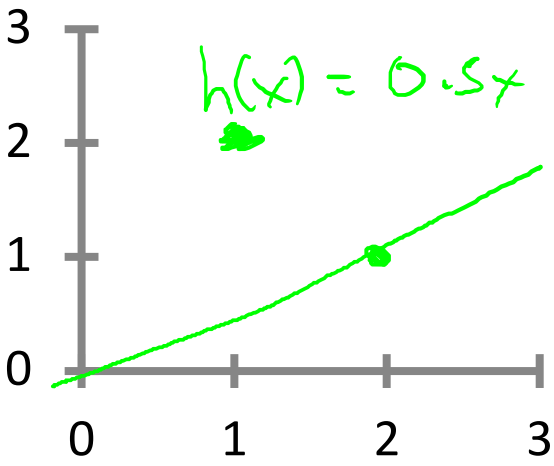
θ_i's: Parameters

How to choose θ_i's ?

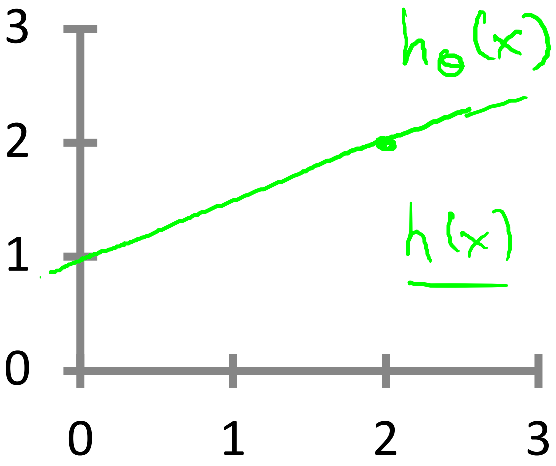
$$h_\theta(x) = \theta_0 + \theta_1 x$$



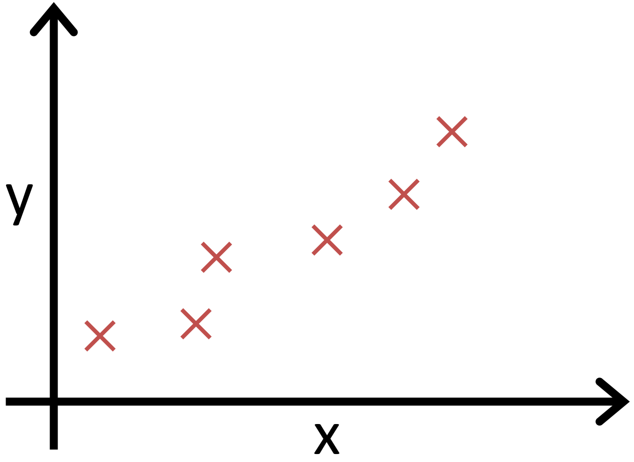
$\theta_0 = 1.5$
$\theta_1 = 0$



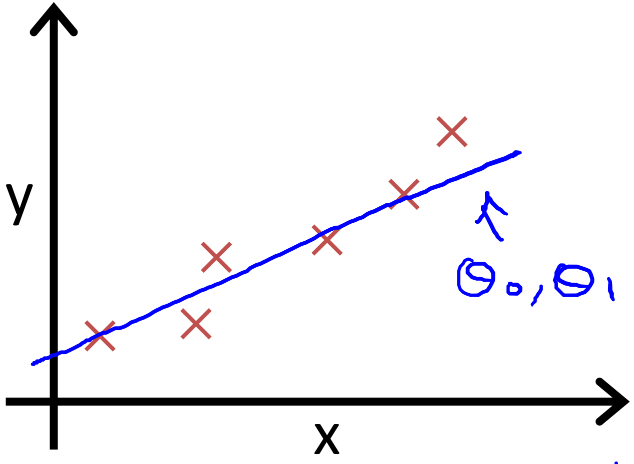
$\theta_0 = 0$
$\theta_1 = 0.5$



$\theta_0 = 1$
$\theta_1 = 0.5$



Idea: Choose θ_0, θ_1 so that
$h_\theta(x)$ is close to y for our
training examples (x, y)



$(x^{(i)}, y^{(i)})$

Idea: Choose θ_0, θ_1 so that $h_\theta(x)$ is close to y for our training examples (x, y)

x, y

training examples

$$\boxed{\underset{\theta_0, \theta_1}{\text{minimize}}} \ \frac{1}{2m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right)^2$$

$$h_\theta(x^{(i)}) = \theta_0 + \theta_1 x^{(i)}$$

$$J(\theta_0, \theta_1) = \frac{1}{2m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right)^2$$

$$\underset{\theta_0, \theta_1}{\text{minimize}} \ \underbrace{J(\theta_0, \theta_1)}_{\text{Cost function}}$$

Squared error function

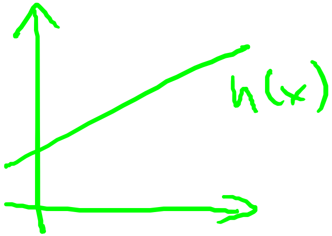
Simplified

Hypothesis:

$$h_\theta(x) = \theta_0 + \theta_1 x$$

Parameters:

$$\theta_0, \theta_1$$



Cost Function:

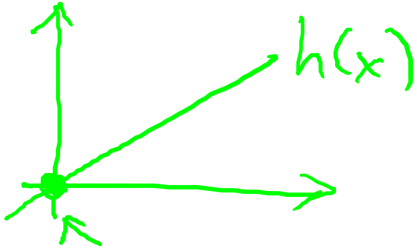
$$\rightarrow J(\theta_0, \theta_1) = \frac{1}{2m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)}\right)^2$$

Goal: $\underset{\theta_0, \theta_1}{\text{minimize}}\ J(\theta_0, \theta_1)$

$$h_\theta(x) = \theta_1 x$$

$\theta_0 = 0$

$$\theta_1$$



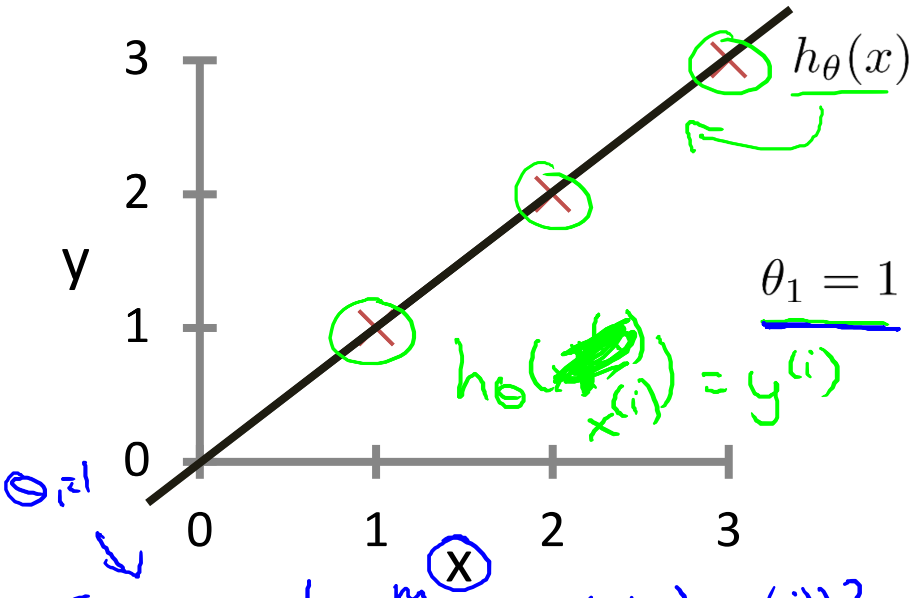
$$J(\theta_1) = \frac{1}{2m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)}\right)^2$$

$\theta, x^{(i)}$

$$\underset{\theta_1}{\text{minimize}}\ J(\theta_1)$$

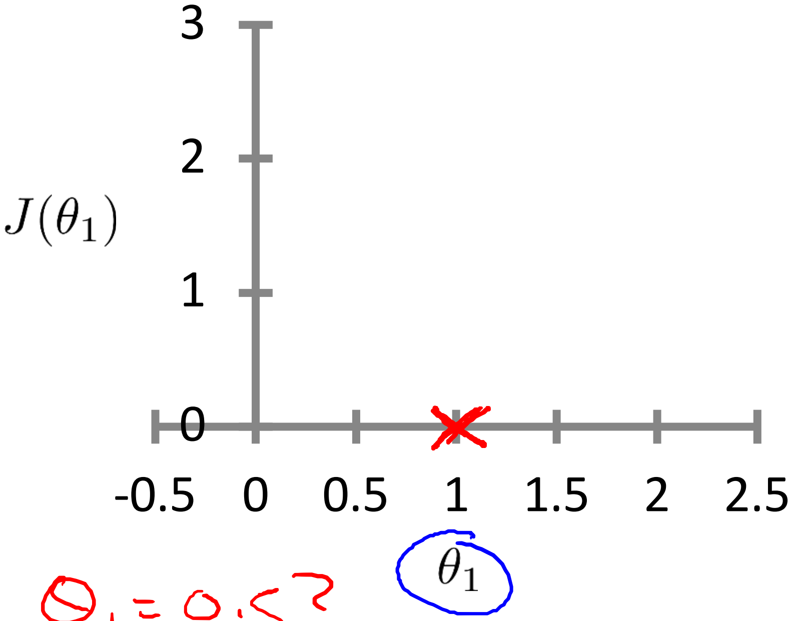
$\rightarrow h_\theta(x)$

(for fixed θ_1, this is a function of x)



$\rightarrow J(\theta_1)$

(function of the parameter θ_1)



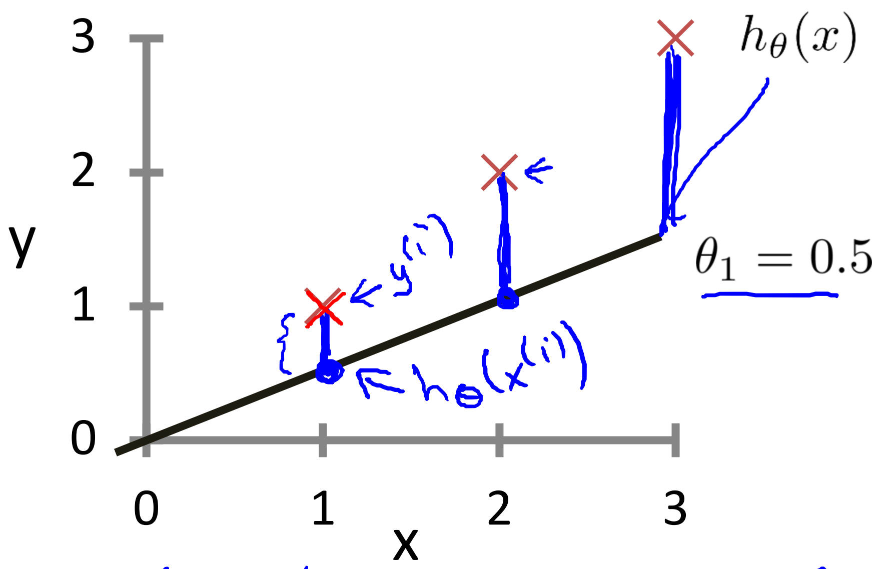
$$J(\theta_1) = \frac{1}{2m}\sum_{i=1}^{m}\left(h_\theta(x^{(i)}) - y^{(i)}\right)^2$$

$$= \frac{1}{2m}\sum_{i=1}^{m}\left(\theta_1 x^{(i)} - y^{(i)}\right)^2 = \frac{1}{2m}\left(0^2+0^2+0^2\right) = 0^2$$

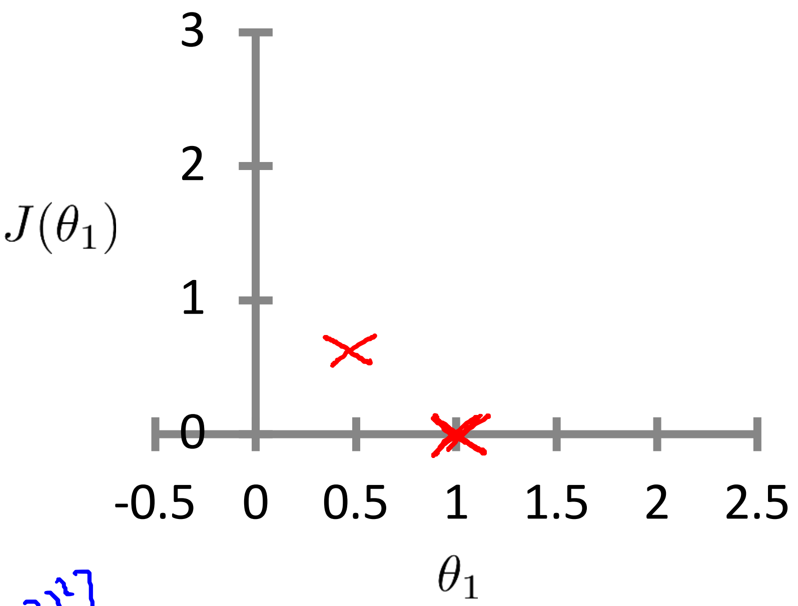
$\theta_1 = 0.5$?

$J(1) = 0$

$h_\theta(x)$ (for fixed θ_1, this is a function of x)



$J(\theta_1)$ (function of the parameter θ_1)



$$J(0.5) = \frac{1}{2m}\left[(0.5-1)^2 + (1-2)^2 + (1.5-3)^2\right]$$

$$= \frac{1}{2\times 3}(3.5) = \frac{3.5}{6} \approx 0.58$$

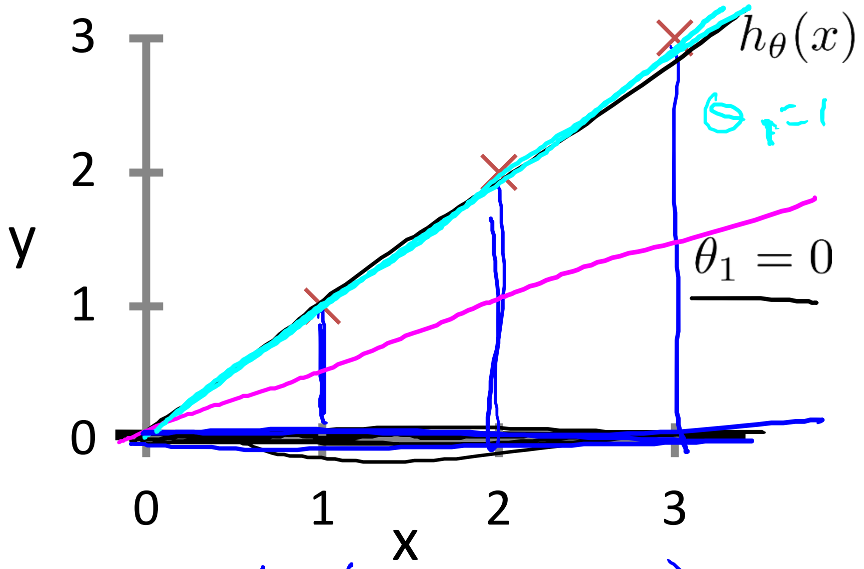
$\theta_1 = 0$?

$J(0) = $?

Andrew Ng

$h_\theta(x)$

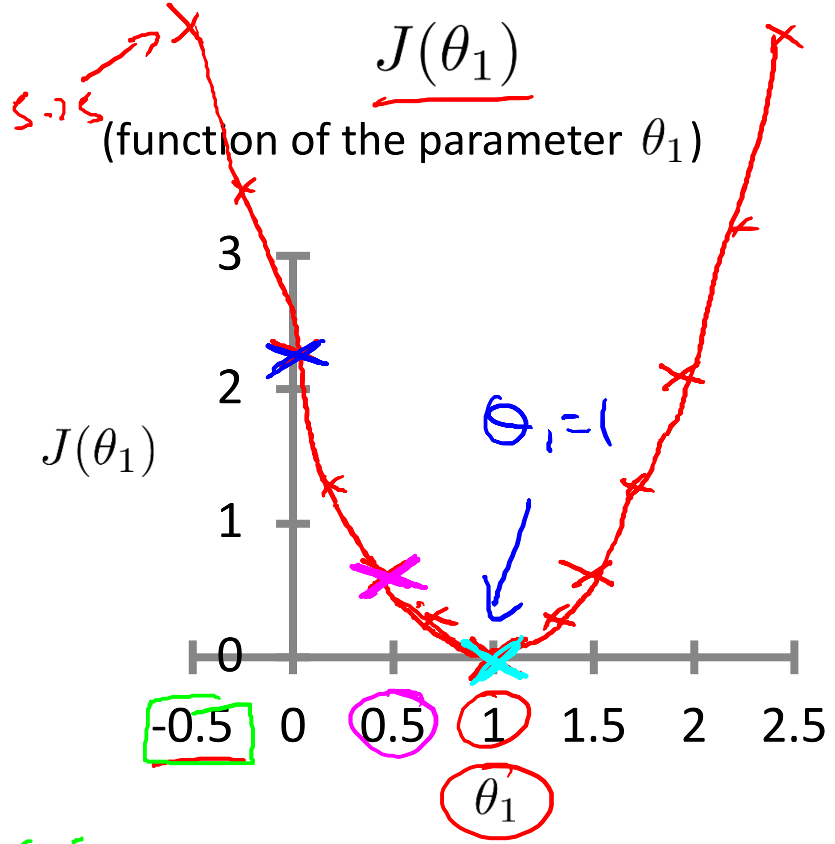
(for fixed θ_1, this is a function of x)



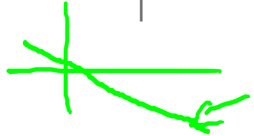
$$J(0) = \frac{1}{2m}(1^2 + 2^2 + 3^2) = \frac{1}{6} \cdot 14 \approx 2.3$$

$J(\theta_1)$

(function of the parameter θ_1)



$h(x) = -0.5x$



$$\boxed{\underset{\theta_1}{\text{minimize}}\; J(\theta_1)}$$

Hypothesis: $h_\theta(x) = \theta_0 + \theta_1 x$

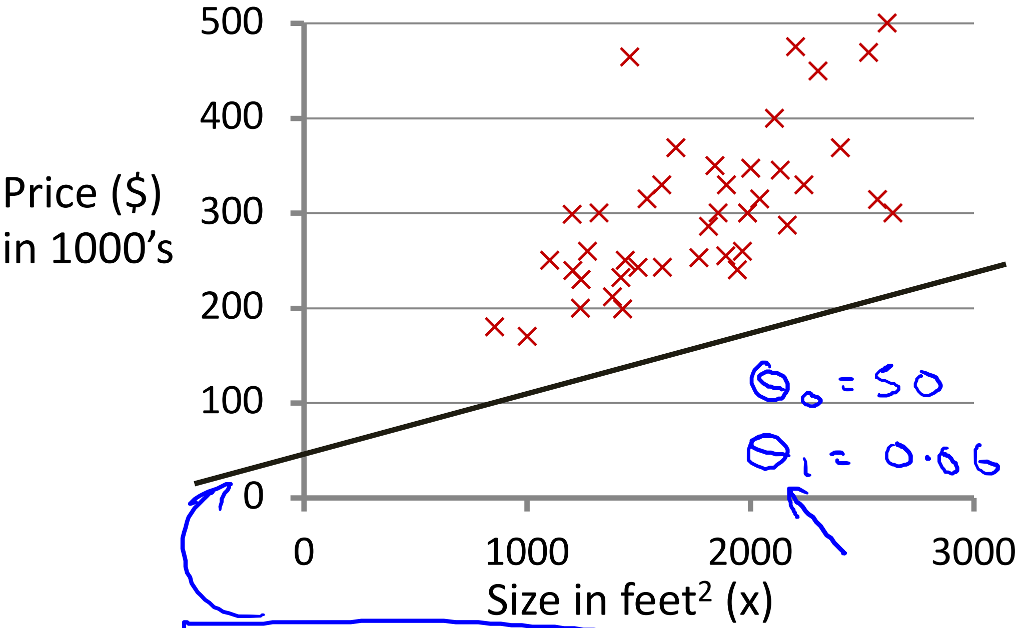
Parameters: θ_0, θ_1

Cost Function: $J(\theta_0, \theta_1) = \frac{1}{2m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right)^2$

Goal: $\underset{\theta_0, \theta_1}{\text{minimize}}\ J(\theta_0, \theta_1)$

$h_\theta(x)$

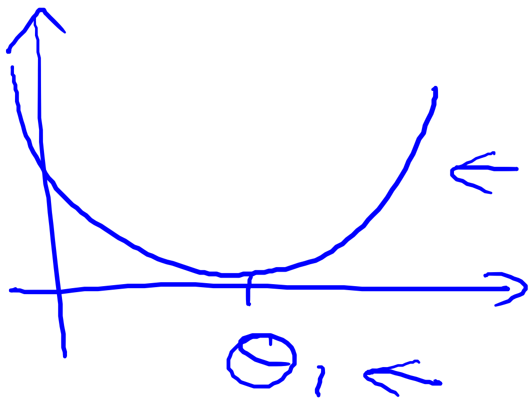
(for fixed θ_0, θ_1, this is a function of x)



$$\boxed{h_\theta(x) = 50 + 0.06x}$$

$J(\theta_0, \theta_1)$

(function of the parameters θ_0, θ_1)



$$\boxed{\theta_0, \theta_1}$$

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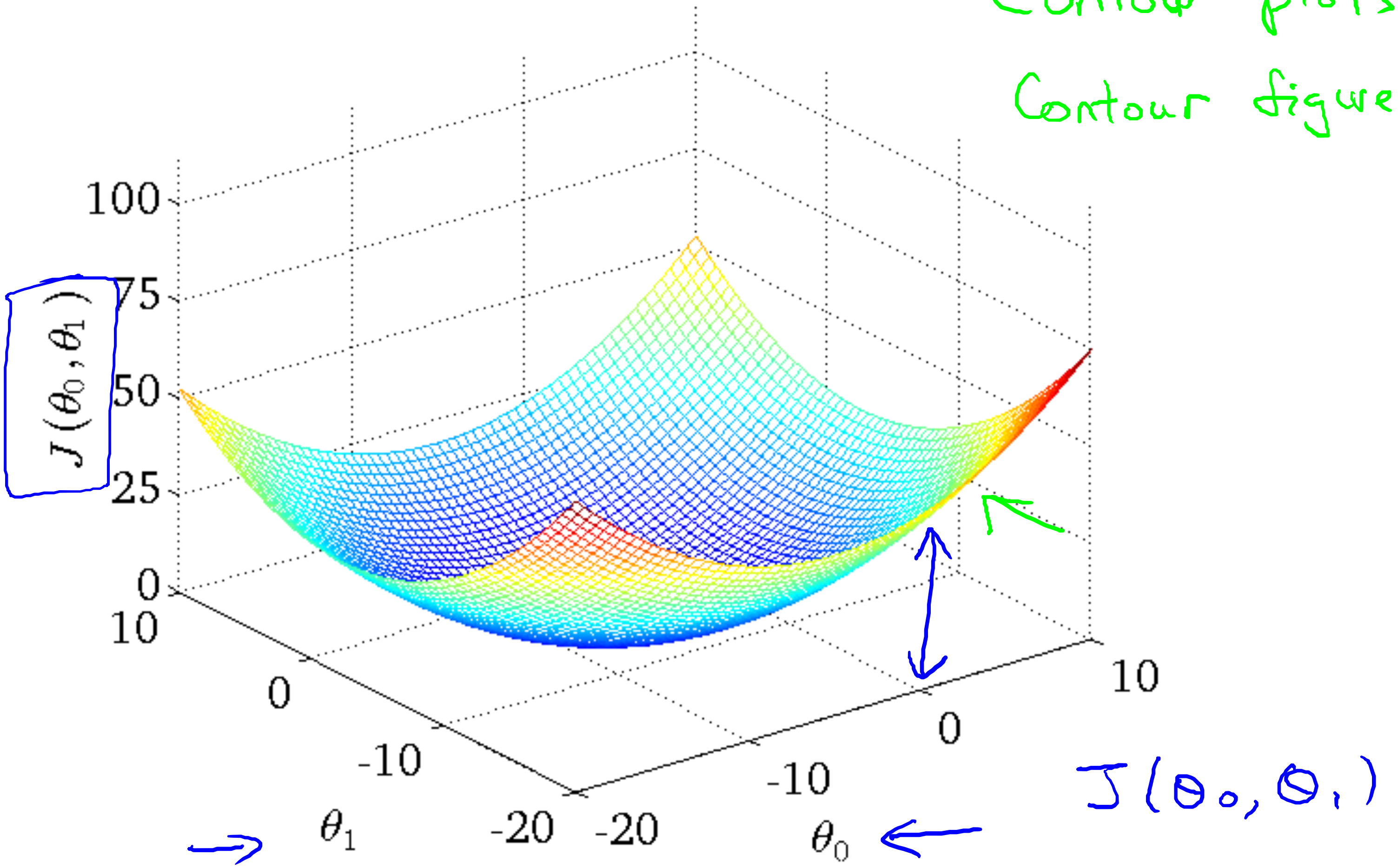
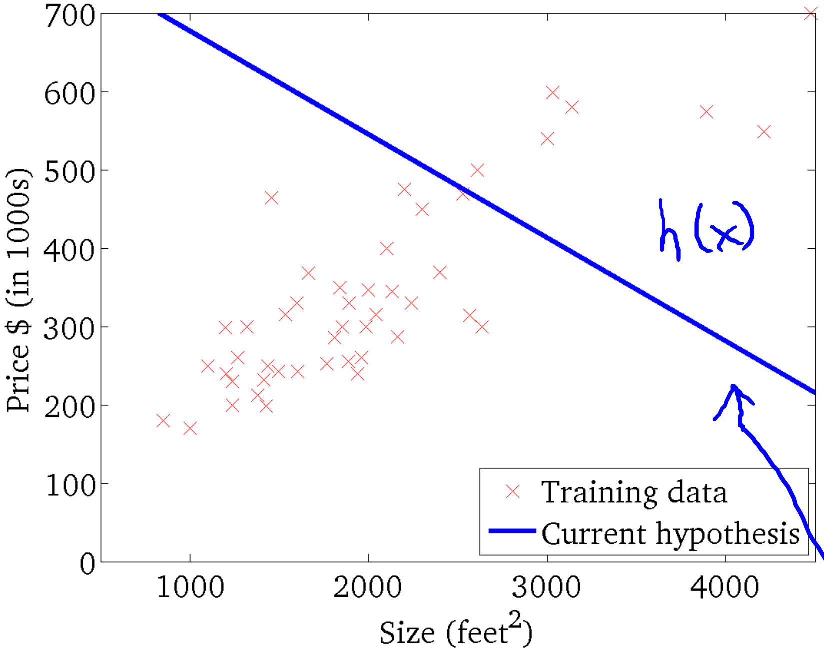
Contour plots
Contour figures -



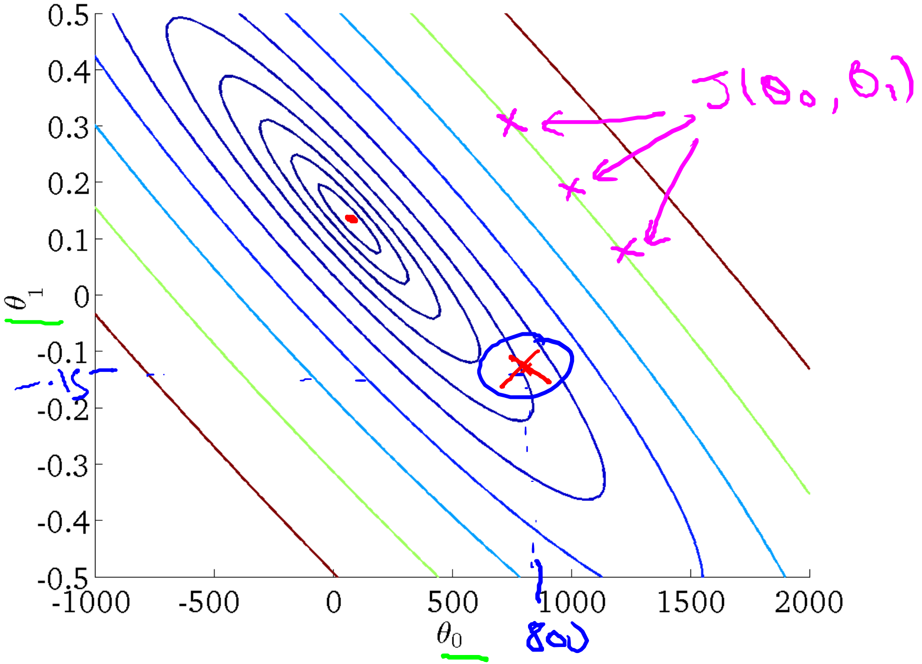
$h_\theta(x)$

(for fixed θ_0, θ_1, this is a function of x)



$J(\theta_0, \theta_1)$

(function of the parameters θ_0, θ_1)



$\underline{\theta_0, \theta_1}$

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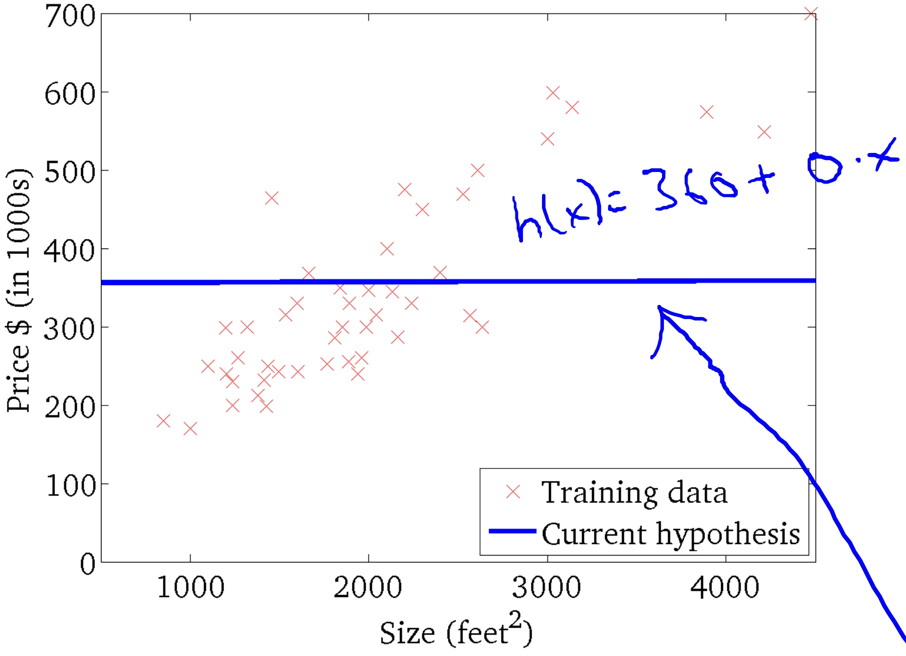
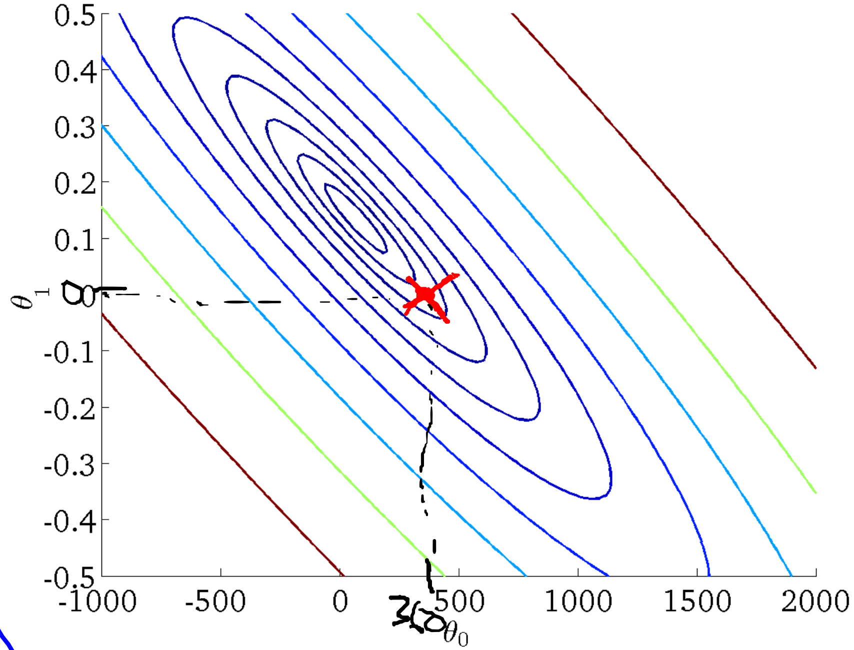
$h_\theta(x)$

(for fixed θ_0, θ_1, this is a function of x)



$J(\theta_0, \theta_1)$

(function of the parameters θ_0, θ_1)



$\theta_0 = 360$

$\theta_1 = 0$

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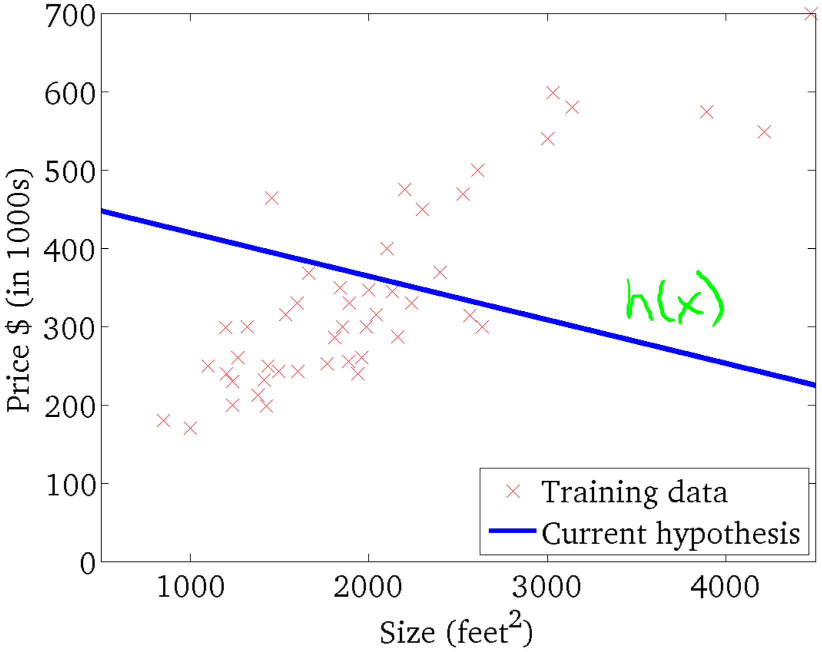
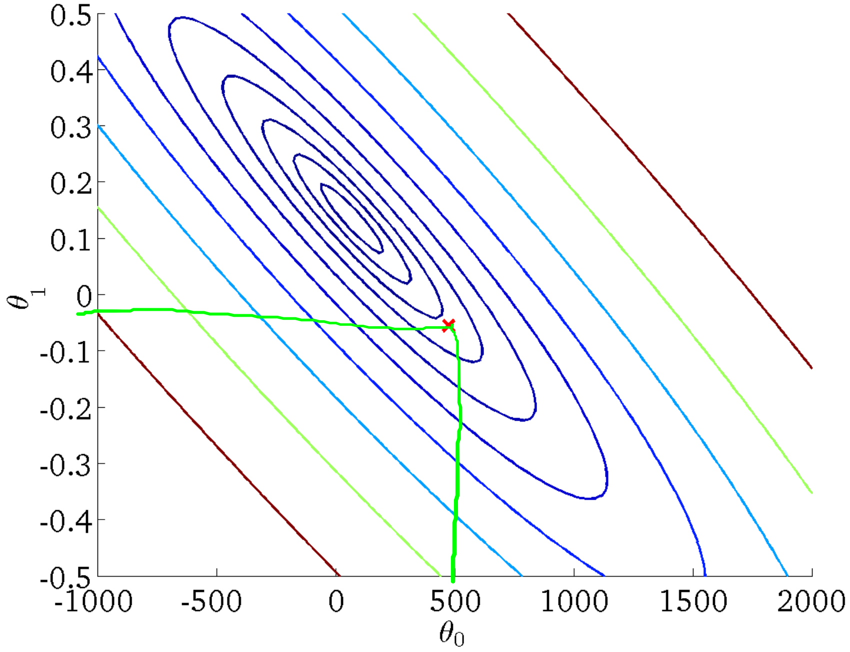
$$h_\theta(x)$$

(for fixed θ_0, θ_1, this is a function of x)



$$J(\theta_0, \theta_1)$$

(function of the parameters θ_0, θ_1)



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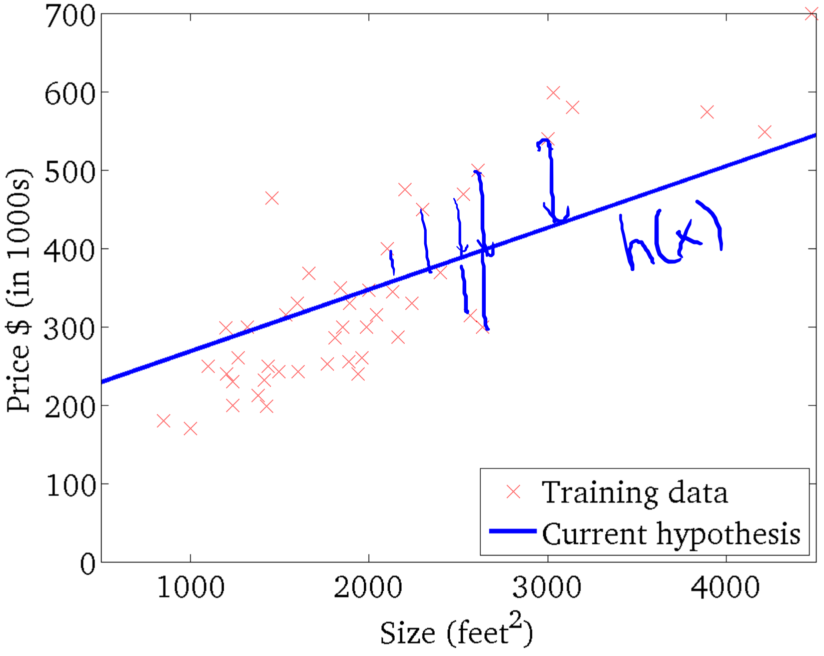
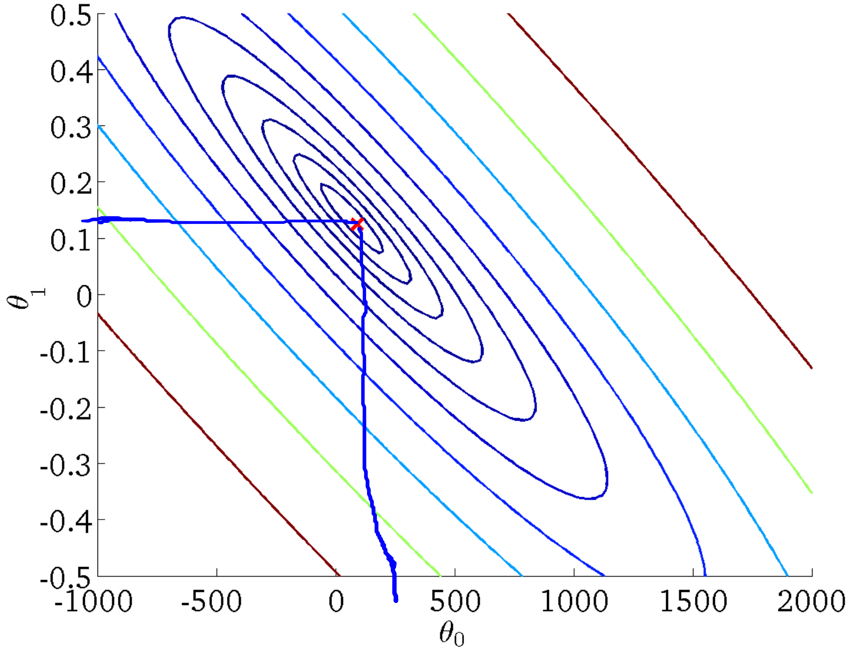
$$h_\theta(x)$$

(for fixed θ_0, θ_1, this is a function of x)



$$J(\theta_0, \theta_1)$$

(function of the parameters θ_0, θ_1)



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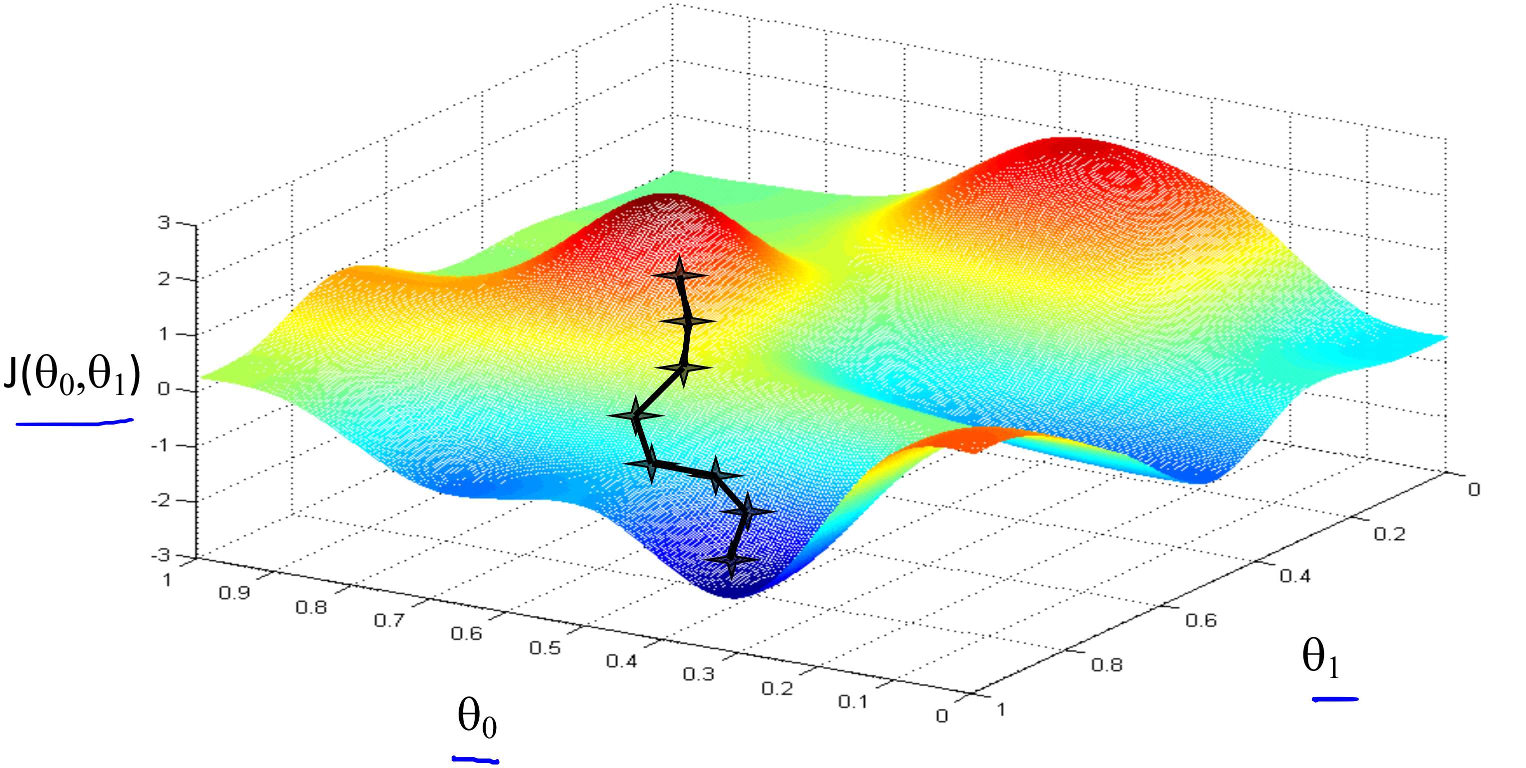
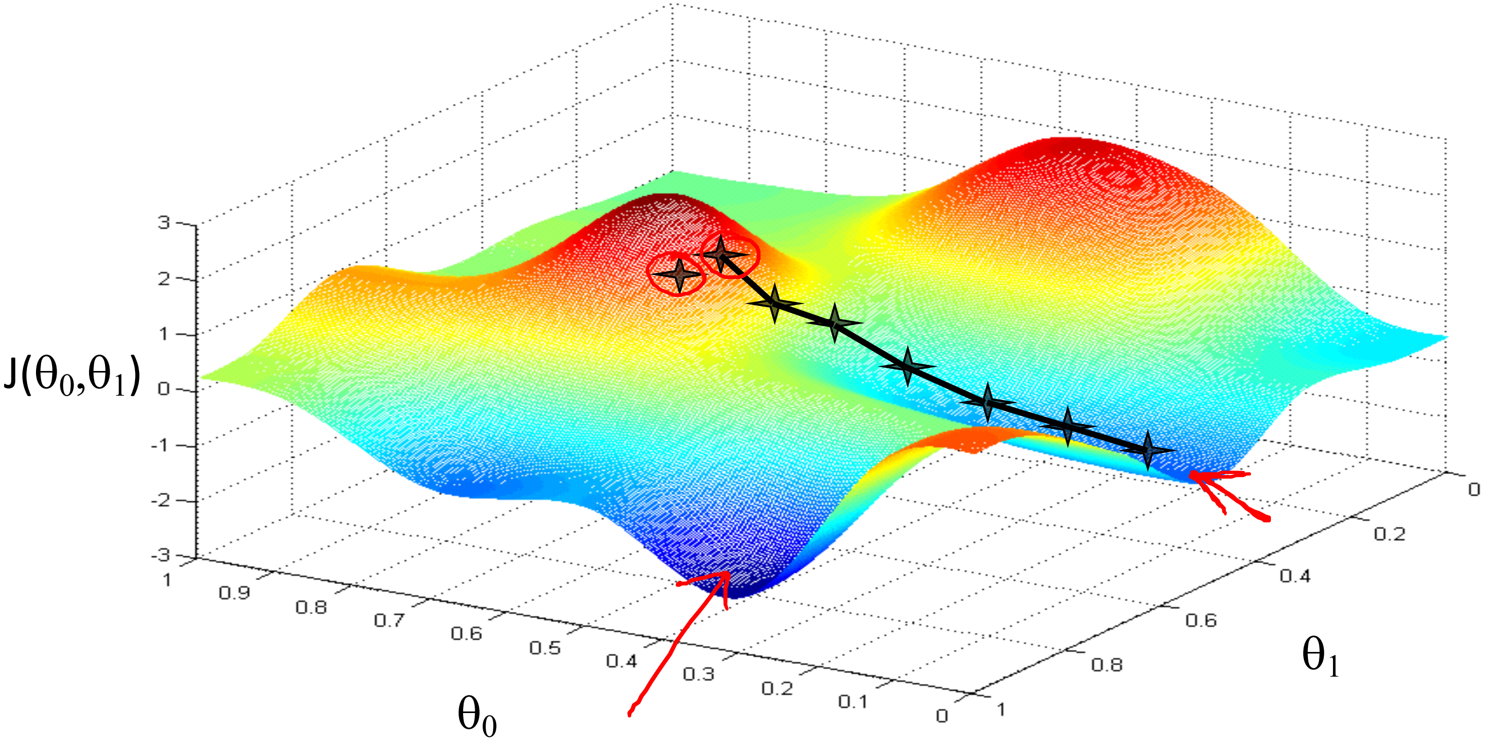
Have some function $J(\theta_0, \theta_1)$ $J(\theta_0, \theta_1, \theta_2, \ldots, \theta_n)$

Want $\min_{\theta_0, \theta_1} J(\theta_0, \theta_1)$ $\min_{\theta_0 \ldots \theta_n} J(\theta_0, \ldots, \theta_n)$

Outline:

- Start with some θ_0, θ_1 (say $\theta_0 = 0, \theta_1 = 0$)
- Keep changing θ_0, θ_1 to reduce $J(\theta_0, \theta_1)$ until we hopefully end up at a minimum


3
2
1
$J(\theta_0,\theta_1)$
0
-1
-2
-3
1
0.9
0.8
0.7
0.6
0.5
0.4
0.3
0.2
0.1
0
θ_0
0
0.2
0.4
0.6
0.8
1
θ_1



$J(\theta_0,\theta_1)$
3
2
1
0
-1
-2
-3
1
0.9
0.8
0.7
0.6
0.5
0.4
0.3
0.2
0.1
0
θ_0
0
0.2
0.4
0.6
0.8
1
θ_1

Gradient descent algorithm

Assignment

$a := b$

$a := a + 1$

Truth assertion

$a = b$

$a = a + 1$

θ_0, θ_1

repeat until convergence {

$$\theta_j := \theta_j - \alpha \frac{\partial}{\partial \theta_j} J(\theta_0, \theta_1) \quad \text{(for } j = 0 \text{ and } j = 1\text{)}$$

}

learning rate

Simultaneously update θ_0 and θ_1

Correct: Simultaneous update

$$\text{temp0} := \theta_0 - \alpha \frac{\partial}{\partial \theta_0} J(\theta_0, \theta_1)$$

$$\text{temp1} := \theta_1 - \alpha \frac{\partial}{\partial \theta_1} J(\theta_0, \theta_1)$$

$$\theta_0 := \text{temp0}$$

$$\theta_1 := \text{temp1}$$

Incorrect:

$$\text{temp0} := \theta_0 - \alpha \frac{\partial}{\partial \theta_0} J(\theta_0, \theta_1)$$

$$\theta_0 := \text{temp0}$$

$$\text{temp1} := \theta_1 - \alpha \frac{\partial}{\partial \theta_1} J(\theta_0, \theta_1)$$

$$\theta_1 := \text{temp1}$$

Gradient descent algorithm

repeat until convergence {

$$\theta_j := \theta_j - \alpha \boxed{\frac{\partial}{\partial \theta_j} J(\theta_0, \theta_1)} \quad \text{(simultaneously update } j = 0 \text{ and } j = 1)$$

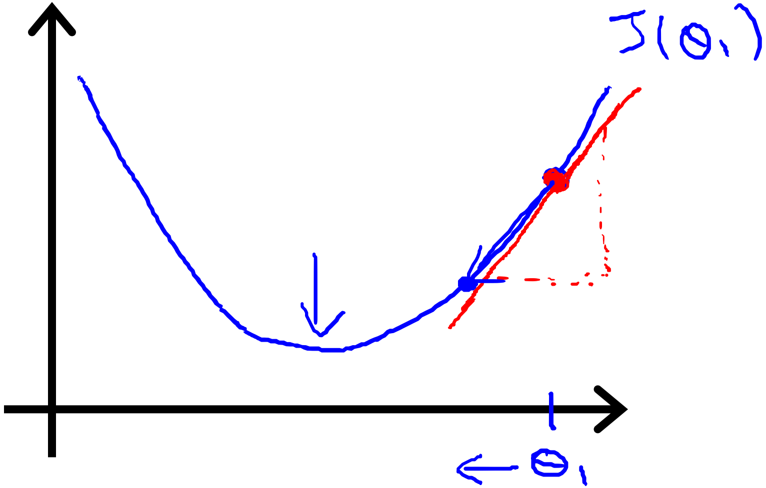
}

learning rate

derivative

$\min_{\theta_1} J(\theta_1)$

$\theta_1 \in \mathbb{R}$.



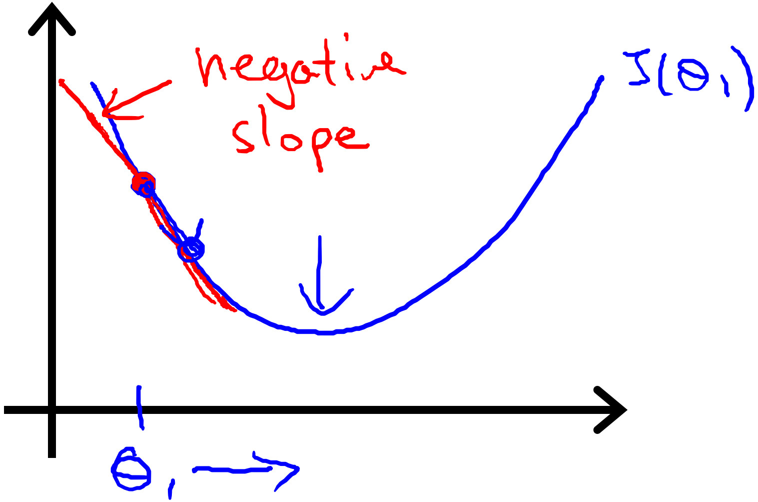
$(\theta_1 \in \mathbb{R})$

$\frac{\partial}{\partial \theta_1}$

$$\theta_1 := \theta_1 - \alpha \boxed{\frac{d}{d\theta_1} J(\theta_1)}$$

≥ 0

$$\theta_1 := \theta_1 - \alpha \cdot (\text{positive number})$$



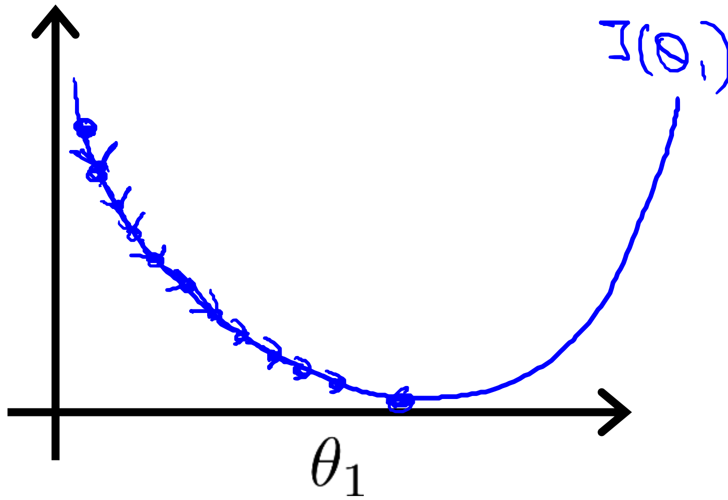
$$\frac{d}{d\theta_1} J(\theta_1)$$

≤ 0

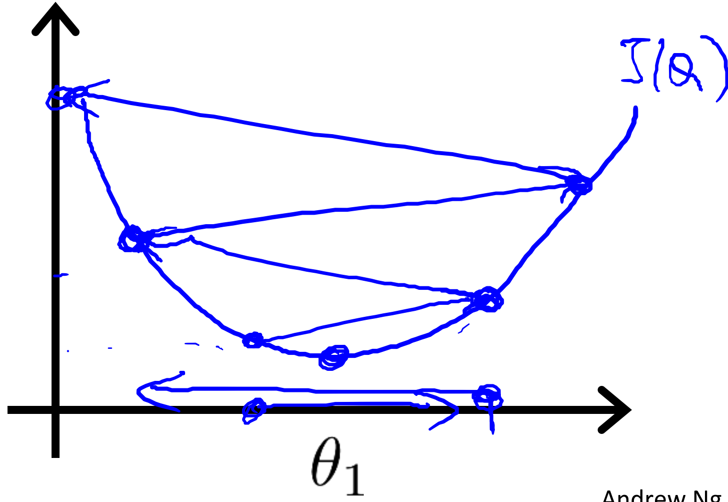
$$\theta_1 := \theta_1 - \alpha \, (\text{negative number})$$

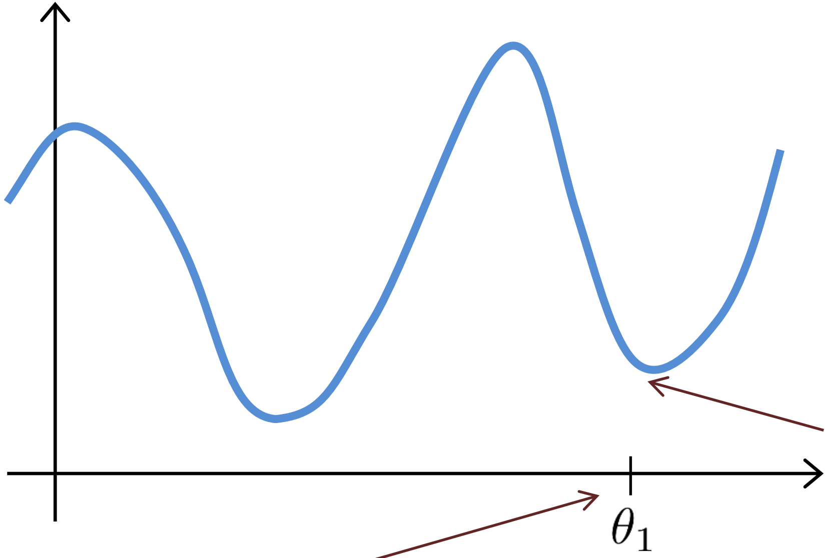
$$\boxed{\theta_1 := \theta_1 - \alpha \frac{\partial}{\partial \theta_1} J(\theta_1)}$$

If α is too small, gradient descent can be slow.



If α is too large, gradient descent can overshoot the minimum. It may fail to converge, or even diverge.





θ_1 at local optima

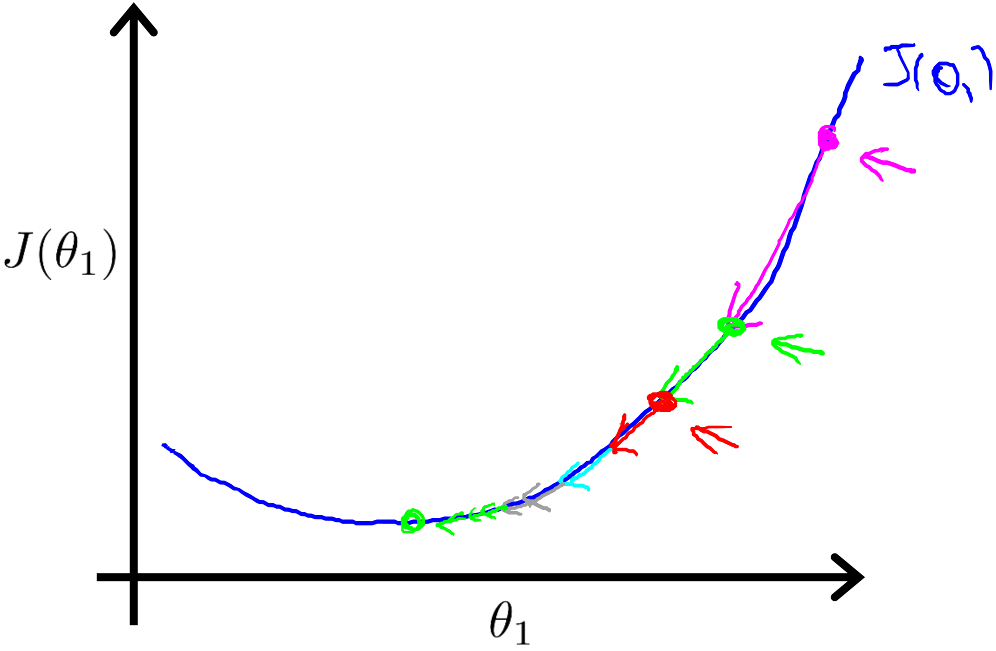
Current value of θ_1

$$\theta_1 := \theta_1 - \alpha \frac{d}{d\theta_1} J(\theta_1)$$

Gradient descent can converge to a local minimum, even with the learning rate α fixed.

$$\theta_1 := \theta_1 - \alpha \boxed{\frac{d}{d\theta_1} J(\theta_1)}$$

As we approach a local minimum, gradient descent will automatically take smaller steps. So, no need to decrease α over time.



Gradient descent algorithm

$$\text{repeat until convergence } \{$$

$$\theta_j := \theta_j - \alpha \frac{\partial}{\partial \theta_j} J(\theta_0, \theta_1)$$

$$(\text{for } j = 1 \text{ and } j = 0)$$

$$\}$$

Linear Regression Model

$$h_\theta(x) = \theta_0 + \theta_1 x$$

$$J(\theta_0, \theta_1) = \frac{1}{2m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right)^2$$

$$\frac{\partial}{\partial \theta_j} \underline{J(\theta_0, \theta_1)} = \frac{\partial}{\partial \theta_j} \underline{\frac{1}{2m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right)^2}$$

$$= \frac{\partial}{\partial \theta_j} \frac{1}{2m} \sum_{i=1}^{m} \left(\underline{\theta_0 + \theta_1 x^{(i)}} - y^{(i)} \right)^2$$

$$j = 0 : \underline{\frac{\partial}{\partial \theta_0} J(\theta_0, \theta_1)} = \frac{1}{m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right)$$

$$j = 1 : \underline{\frac{\partial}{\partial \theta_1} J(\theta_0, \theta_1)} = \frac{1}{m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right) \cdot x^{(i)}$$

Gradient descent algorithm

$\frac{\partial}{\partial \theta_0} J(\theta_0, \theta_1)$

repeat until convergence {

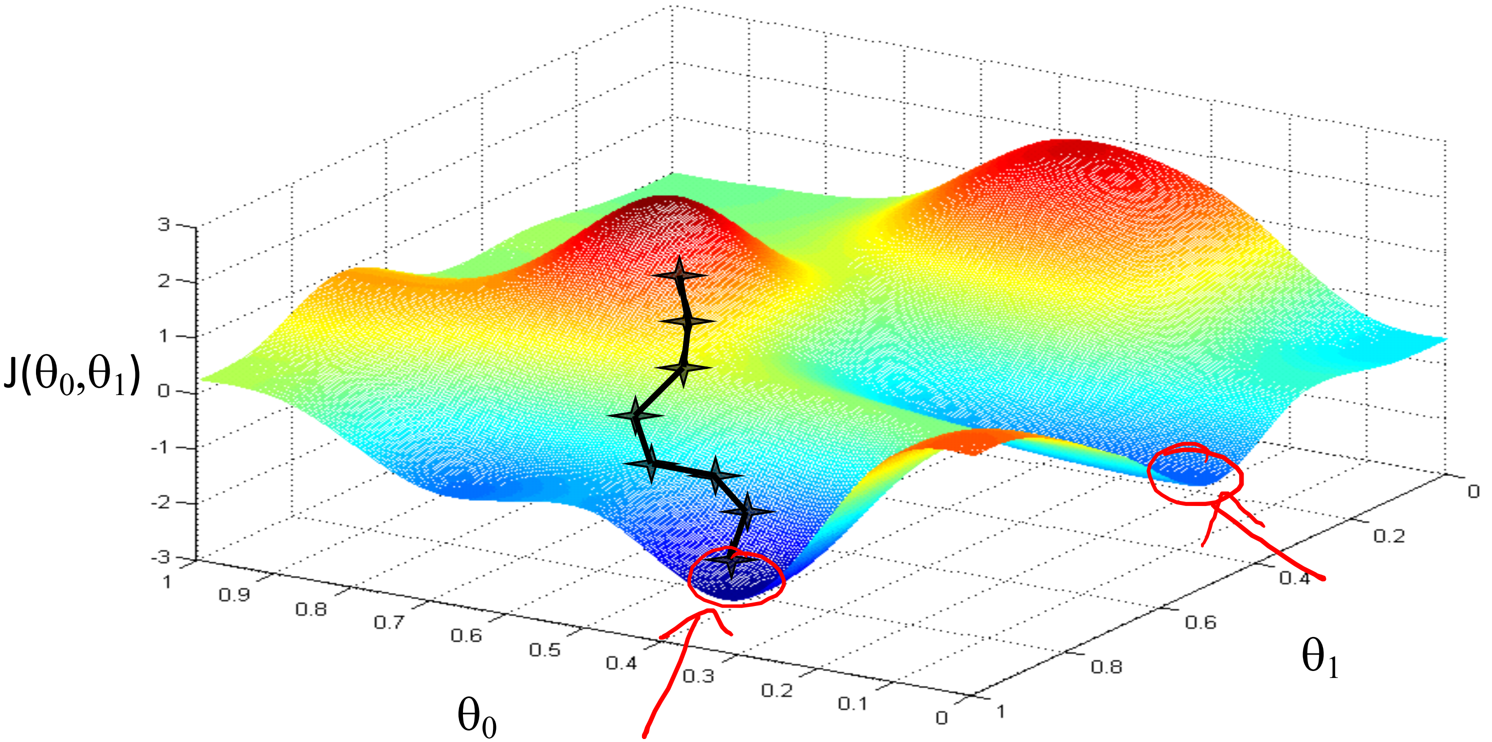
$$\theta_0 := \theta_0 - \alpha \boxed{\frac{1}{m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right)}$$

$$\theta_1 := \theta_1 - \alpha \boxed{\frac{1}{m} \sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right) \cdot x^{(i)}}$$

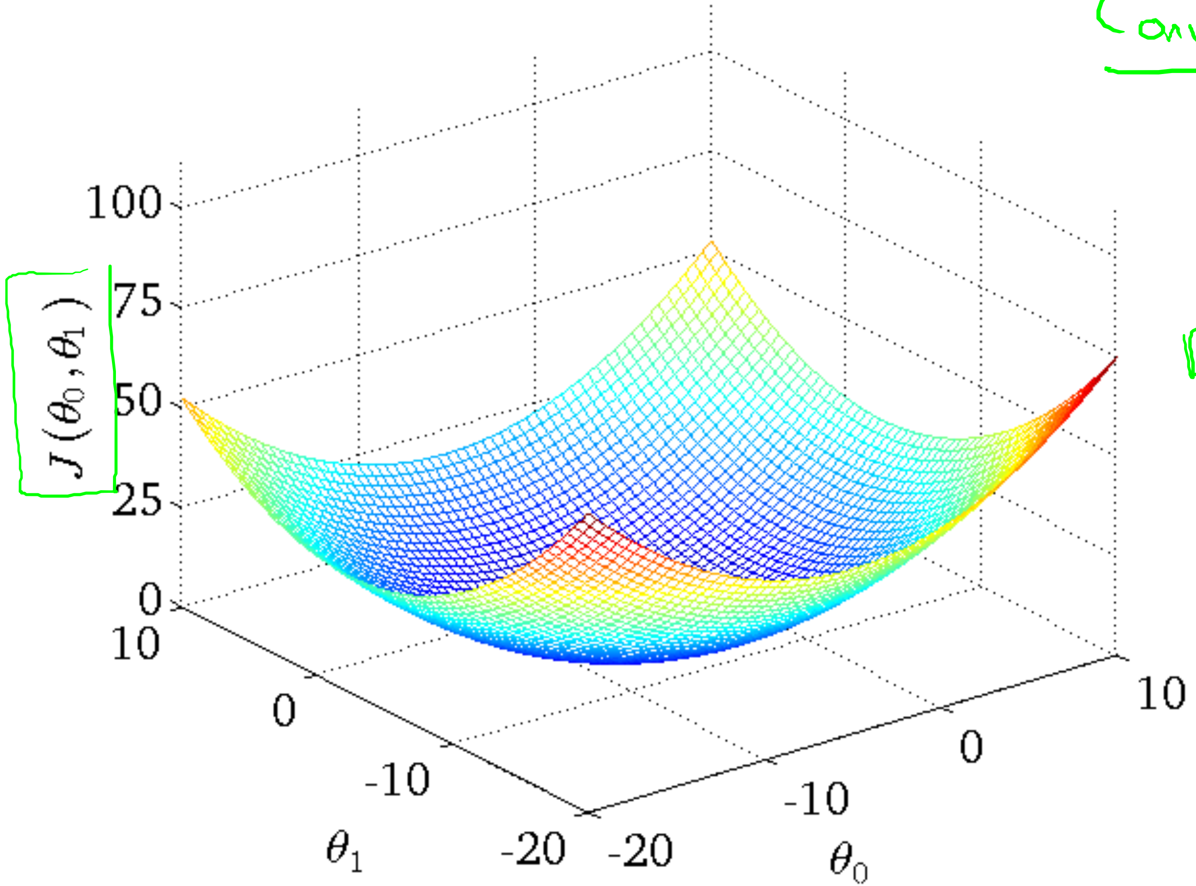
}

$\frac{\partial}{\partial \theta_1} J(\theta_0, \theta_1)$

update θ_0 and θ_1 simultaneously



$J(\theta_0,\theta_1)$
3
2
1
0
-1
-2
-3
1
0.9
0.8
0.7
0.6
0.5
0.4
0.3
0.2
0.1
0
θ_0
0
0.2
0.4
0.6
0.8
1
θ_1

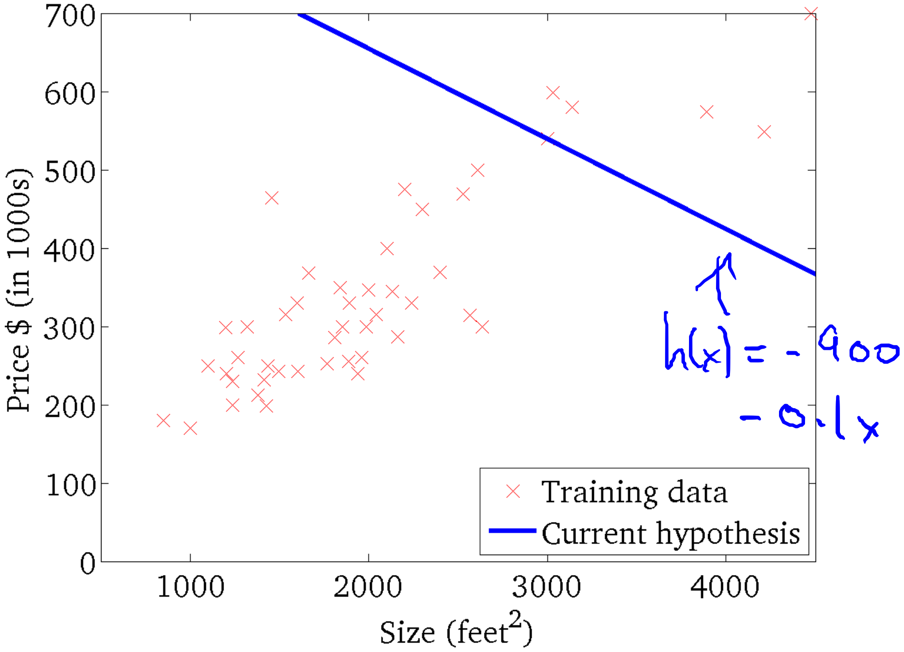


"Convex function"

Bowl-shaped

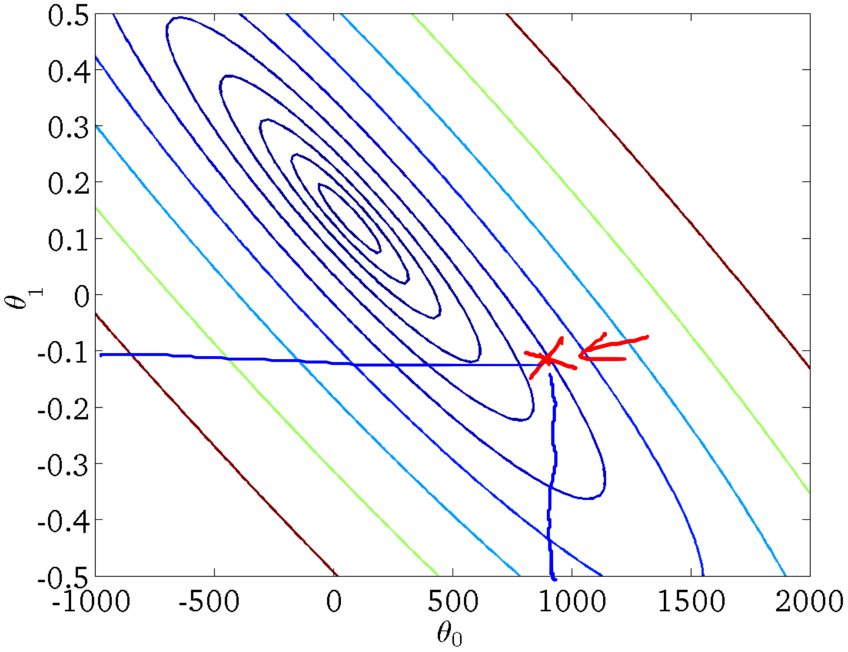
$h_\theta(x)$

(for fixed θ_0, θ_1, this is a function of x)



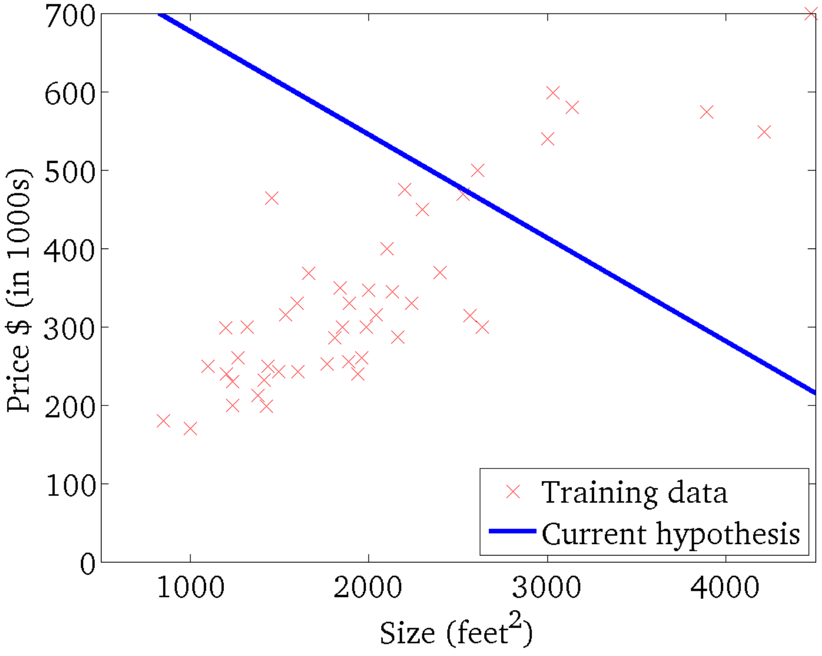
$J(\theta_0, \theta_1)$

(function of the parameters θ_0, θ_1)



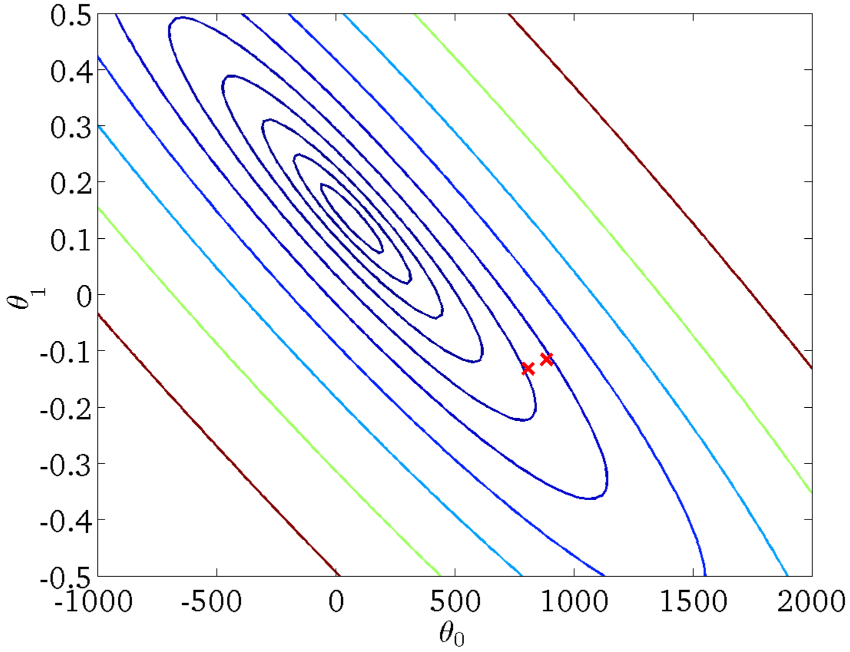
$h_\theta(x)$

(for fixed θ_0, θ_1, this is a function of x)



$J(\theta_0, \theta_1)$

(function of the parameters θ_0, θ_1)



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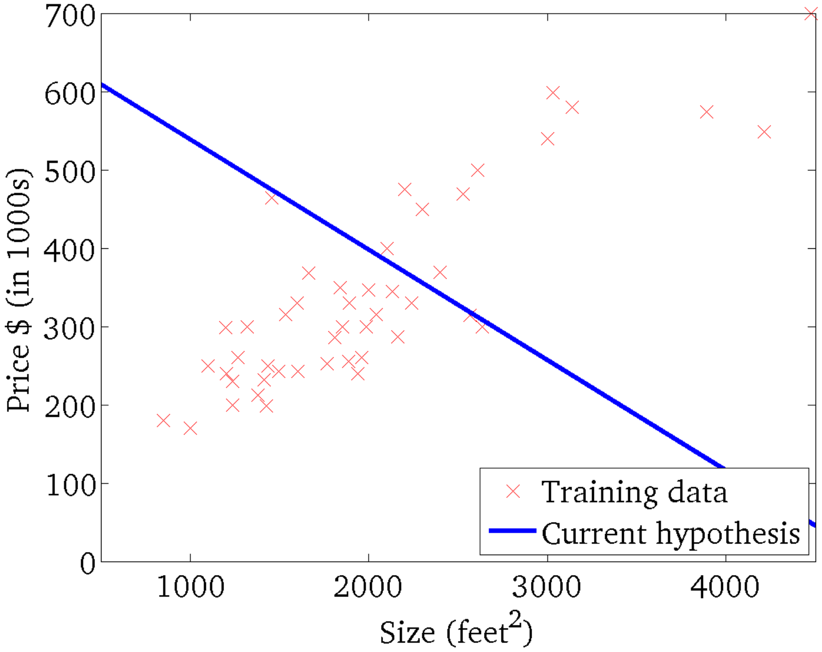
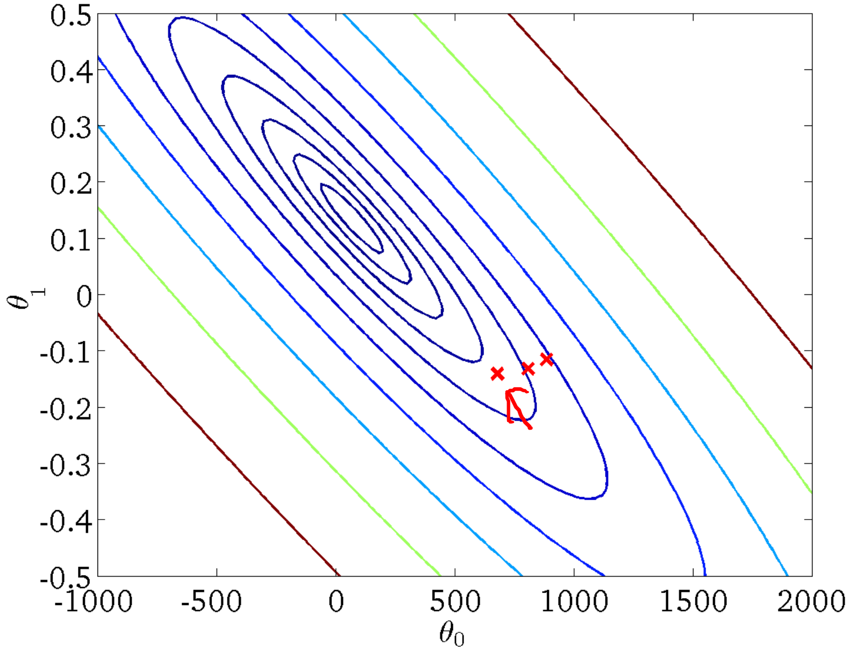
$h_\theta(x)$

(for fixed θ_0, θ_1, this is a function of x)



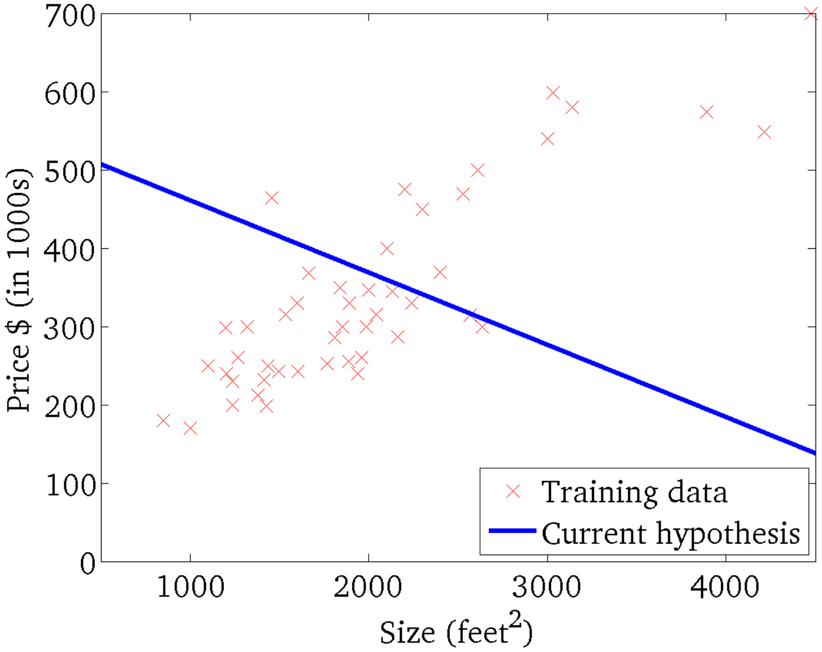
$J(\theta_0, \theta_1)$

(function of the parameters θ_0, θ_1)



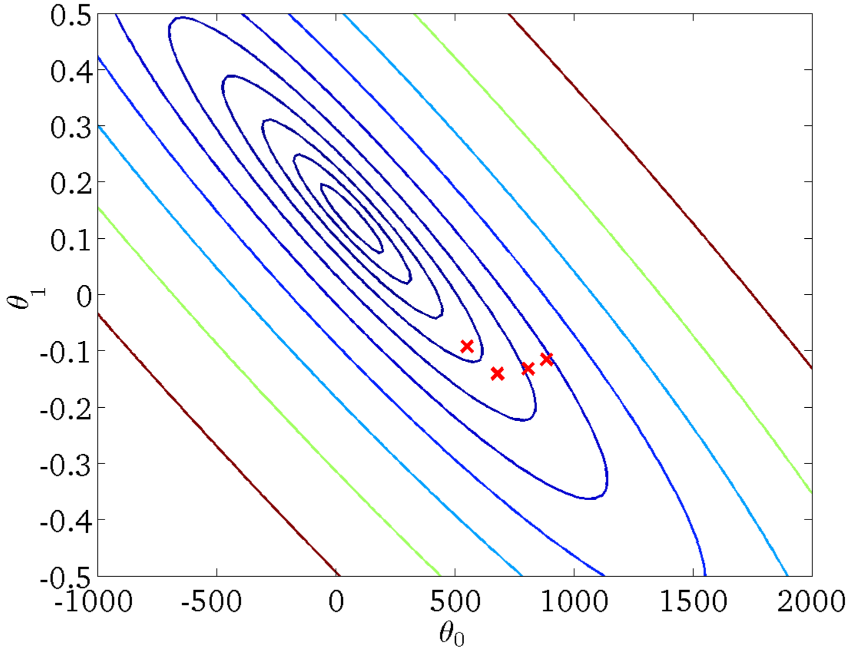
$h_\theta(x)$

(for fixed θ_0, θ_1, this is a function of x)



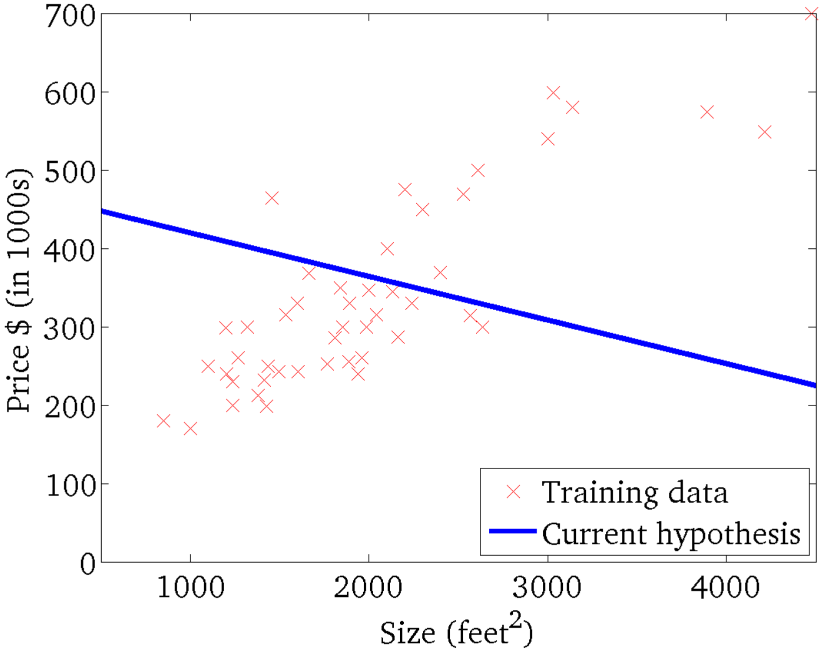
$J(\theta_0, \theta_1)$

(function of the parameters θ_0, θ_1)



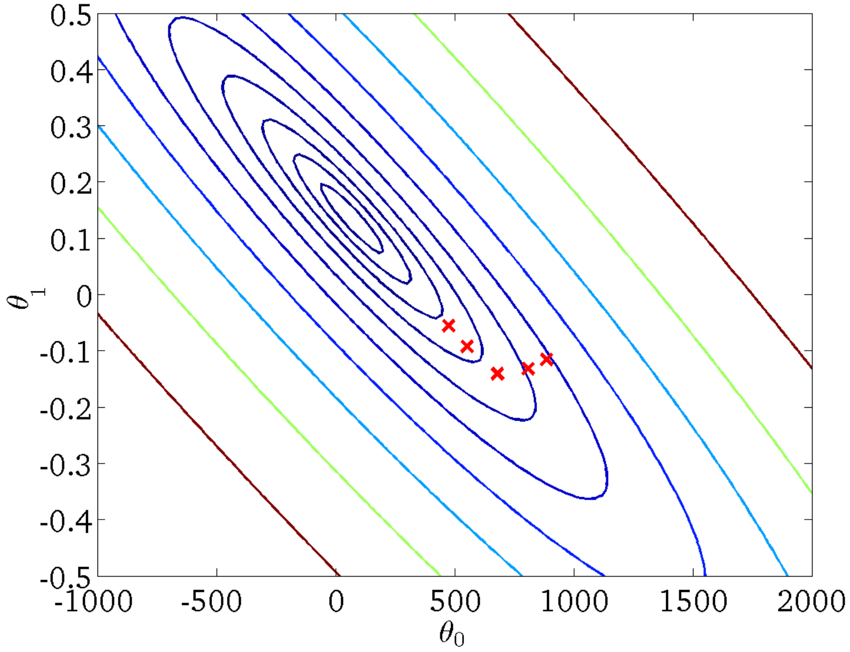
$$h_\theta(x)$$

(for fixed θ_0, θ_1, this is a function of x)



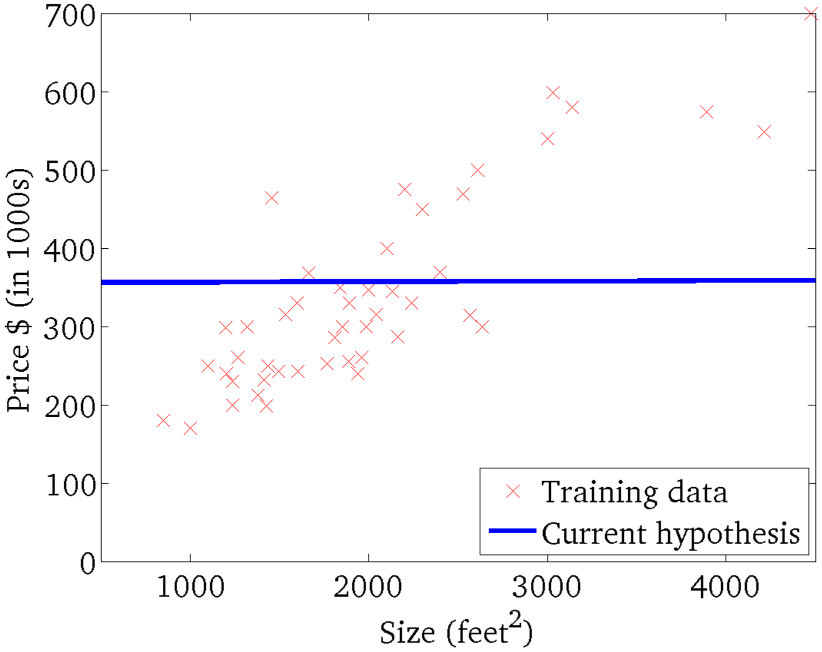
$$J(\theta_0, \theta_1)$$

(function of the parameters θ_0, θ_1)



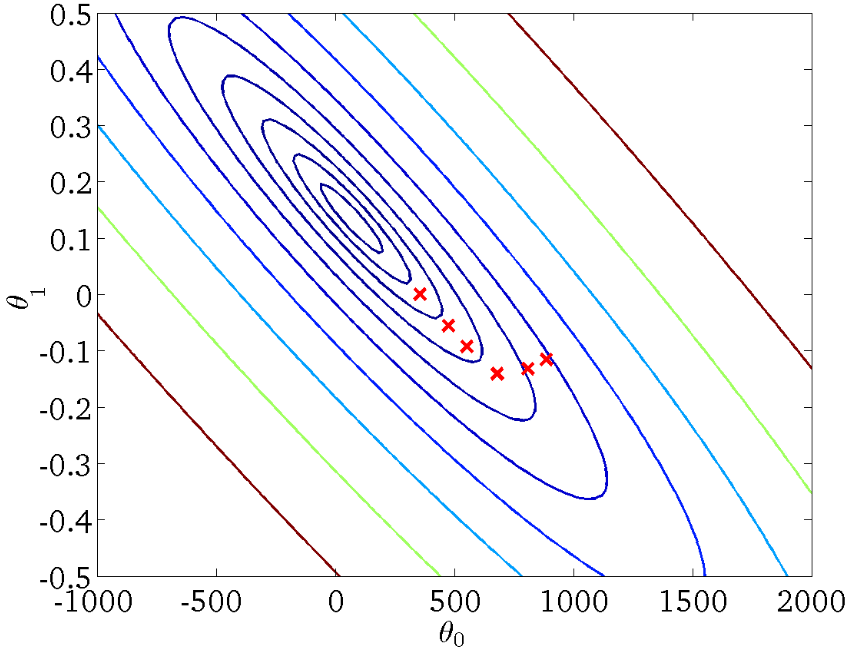
$$h_\theta(x)$$

(for fixed θ_0, θ_1, this is a function of x)



$$J(\theta_0, \theta_1)$$

(function of the parameters θ_0, θ_1)



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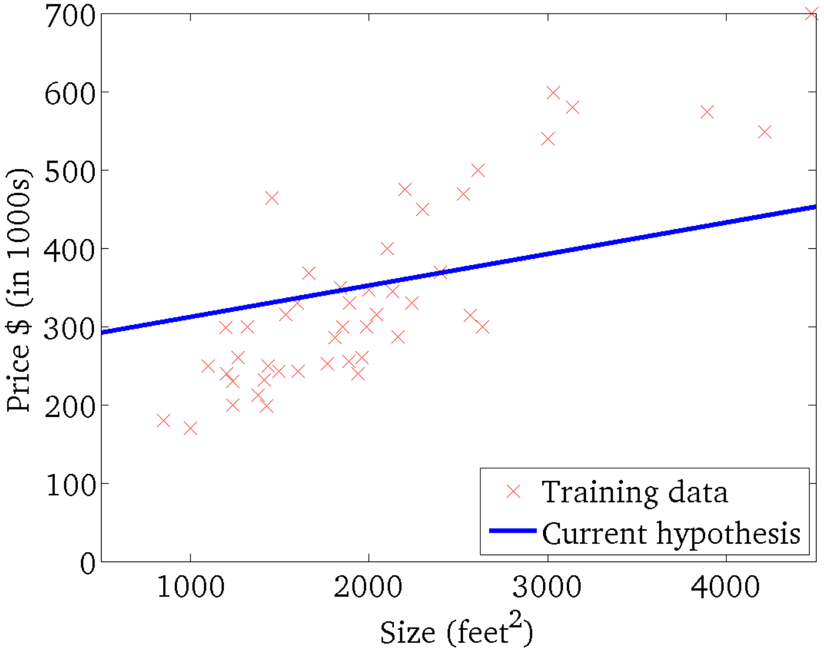
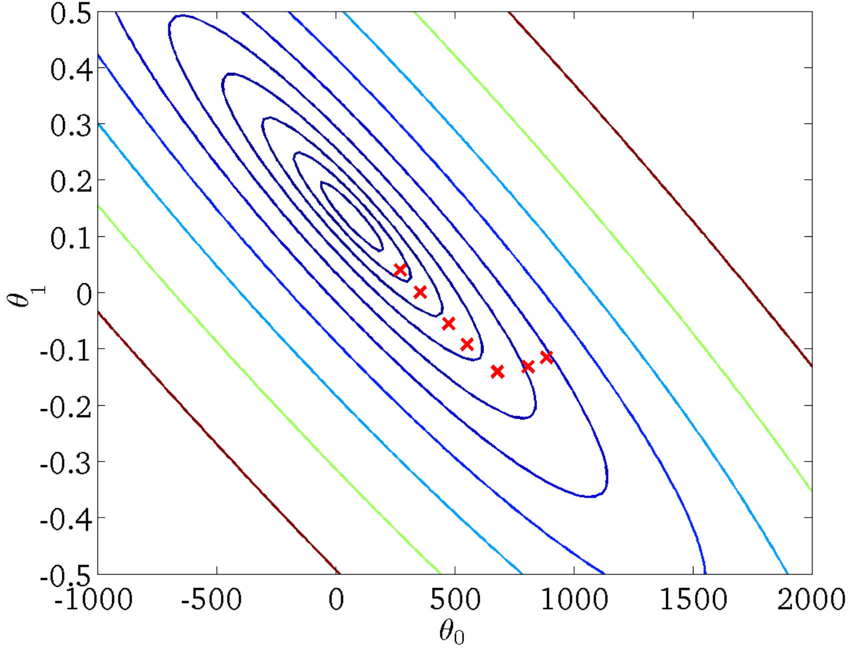
$$h_\theta(x)$$

(for fixed θ_0, θ_1, this is a function of x)



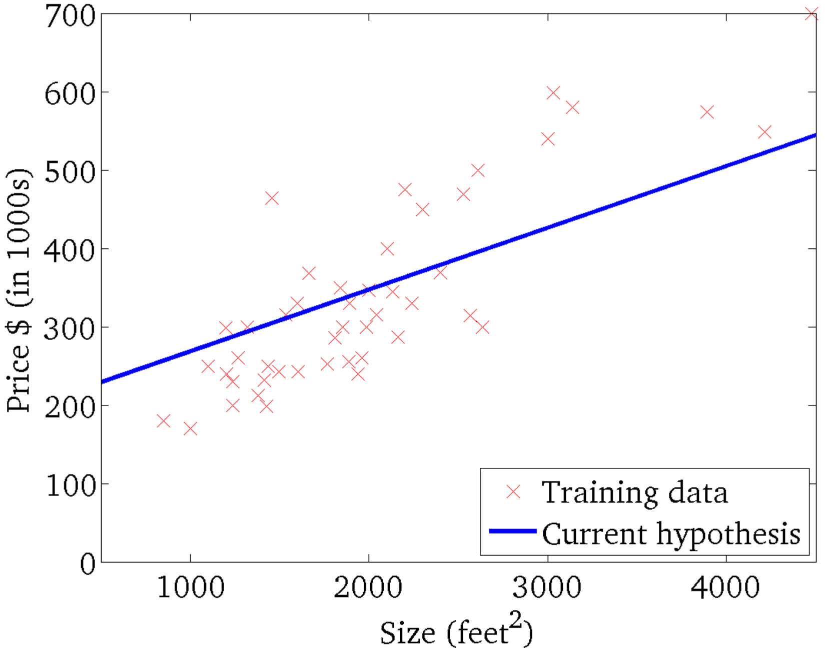
$$J(\theta_0, \theta_1)$$

(function of the parameters θ_0, θ_1)



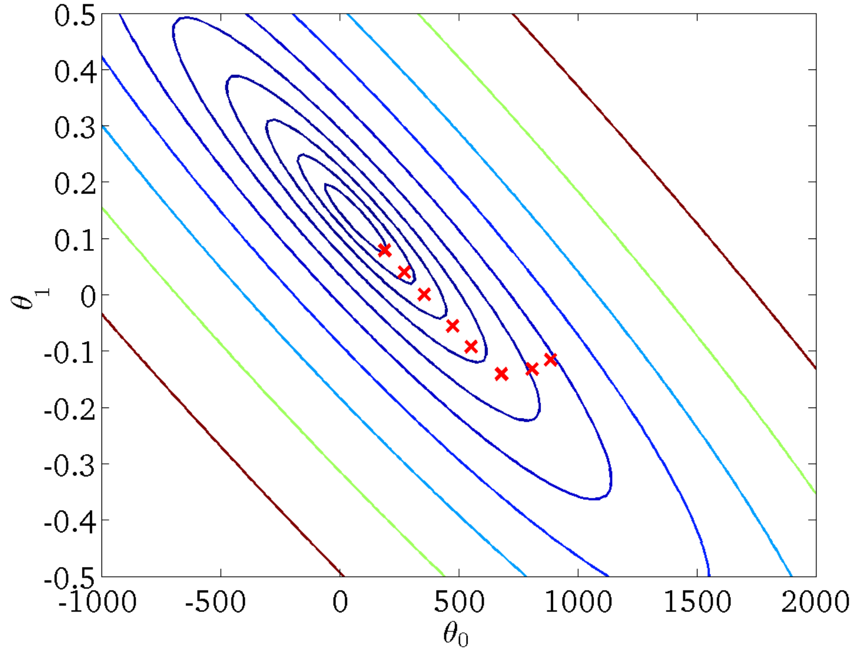
$$h_\theta(x)$$

(for fixed θ_0, θ_1, this is a function of x)



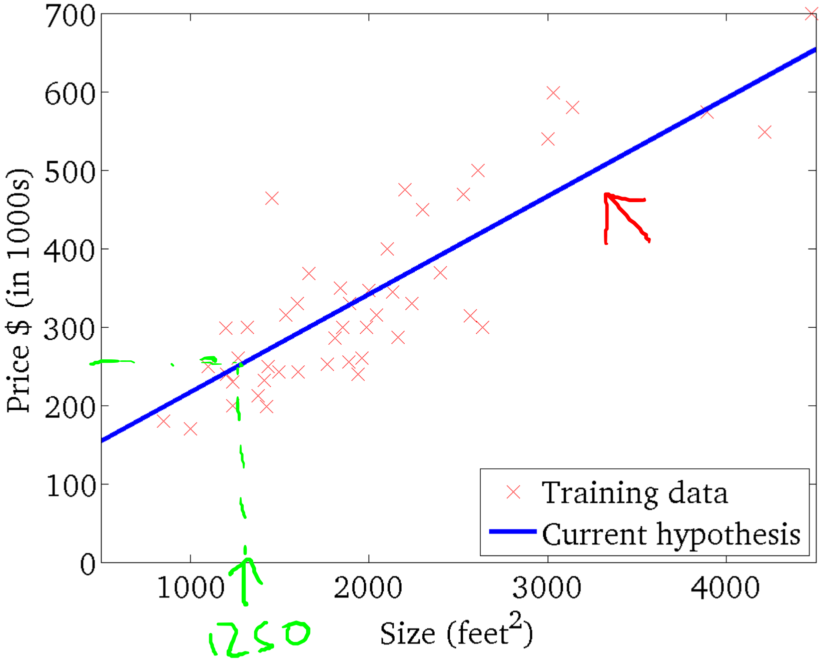
$$J(\theta_0, \theta_1)$$

(function of the parameters θ_0, θ_1)



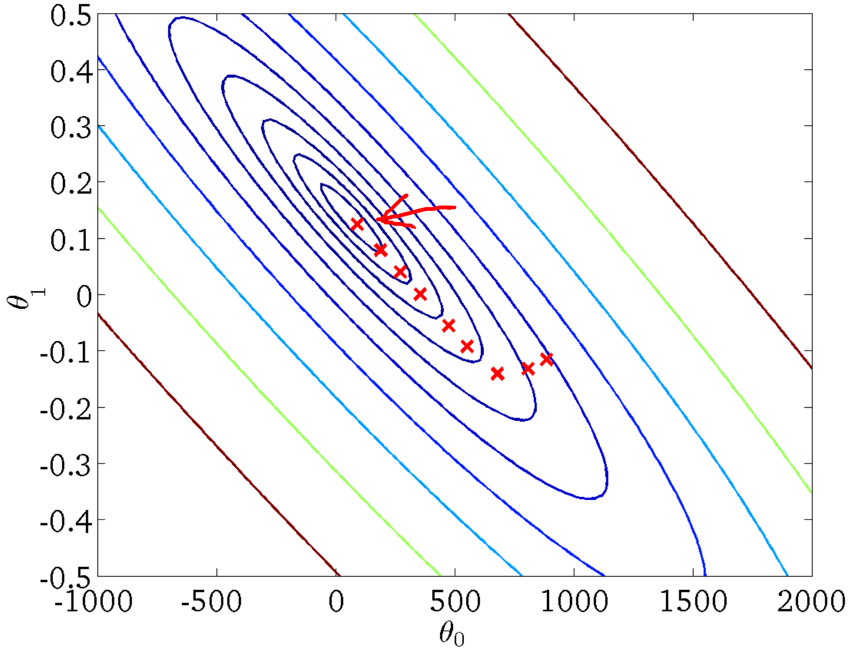
$h_\theta(x)$

(for fixed θ_0, θ_1, this is a function of x)



$J(\theta_0, \theta_1)$

(function of the parameters θ_0, θ_1)



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“Batch” Gradient Descent

“Batch”: Each step of gradient descent uses all the training examples.

$$\sum_{i=1}^{m} \left(h_\theta(x^{(i)}) - y^{(i)} \right)$$

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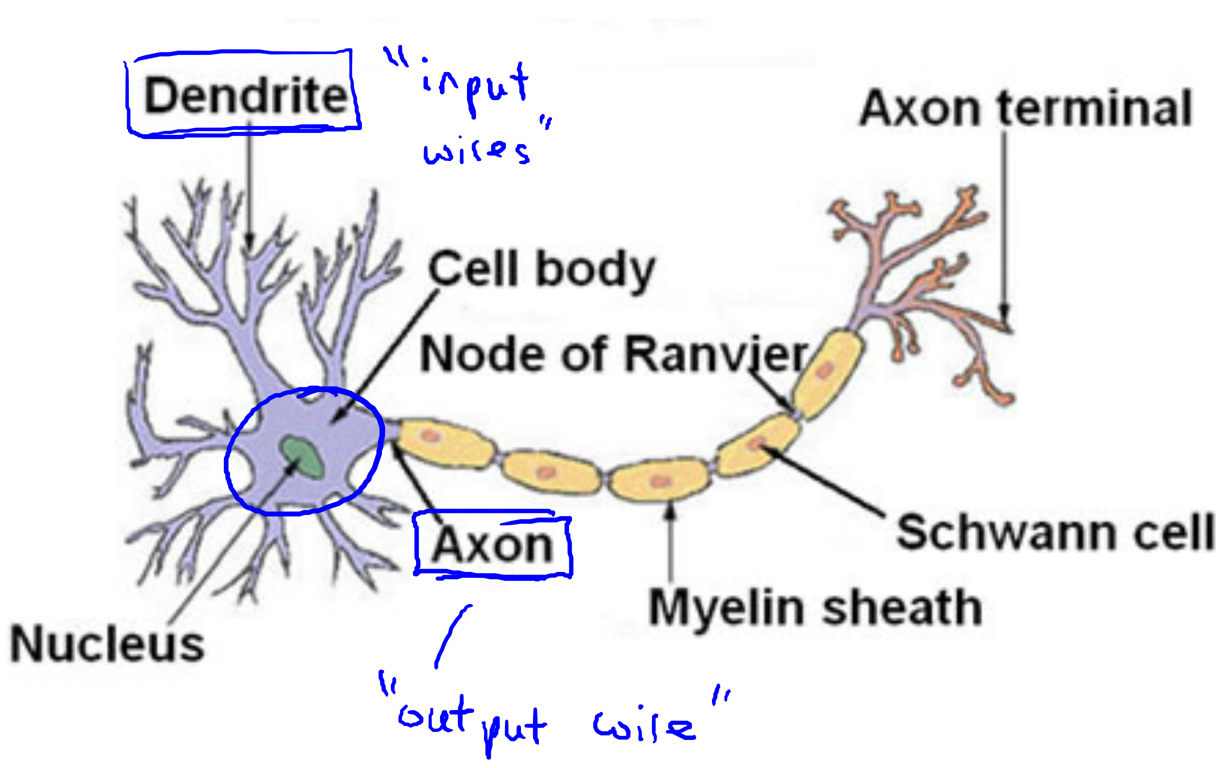
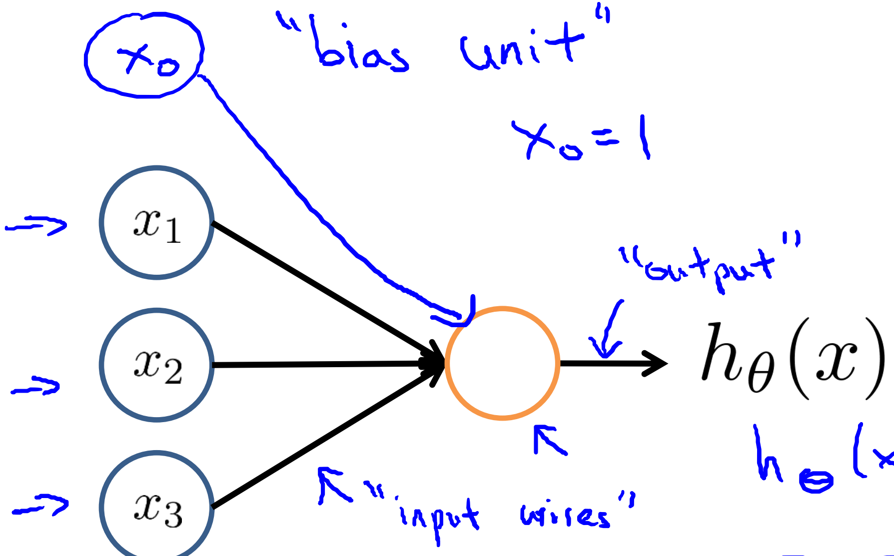
Neural Networks

- Origins: Algorithms that try to mimic the brain.
- Was very widely used in 80s and early 90s; popularity diminished in late 90s.
- Recent resurgence: State-of-the-art technique for many applications

Neuron in the brain



Neuron model: Logistic unit



$$x = \begin{bmatrix} x_0 \\ x_1 \\ x_2 \\ x_3 \end{bmatrix} \qquad \theta = \begin{bmatrix} \theta_0 \\ \theta_1 \\ \theta_2 \\ \theta_3 \end{bmatrix}$$

"weights"

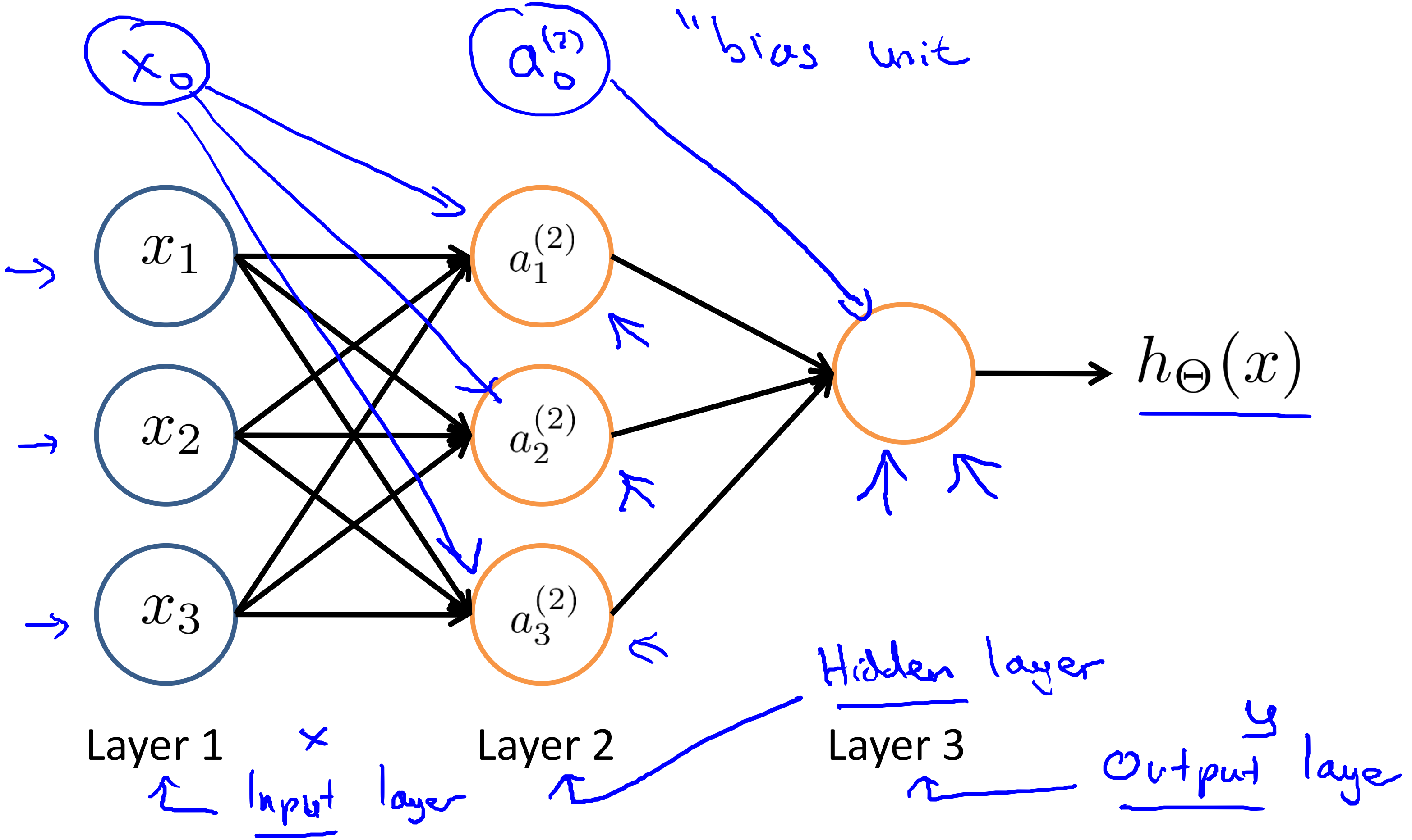
(parameters)

$$h_\theta(x) = \frac{1}{1 + e^{-\theta^T x}}$$

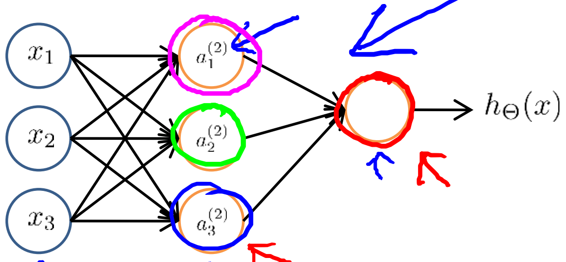
Sigmoid (logistic) activation function.

$$g(z) = \frac{1}{1 + e^{-z}}$$

Neural Network



Neural Network



3 units 3 hidden units

$\rightarrow$ $a_i^{(j)}$ = "activation" of unit i in layer j

$\rightarrow$ $\Theta^{(j)}$ = matrix of weights controlling function mapping from layer j to layer $j+1$

$\Theta^{(1)} \in \mathbb{R}^{3\times 4}$ $h_\Theta(x)$

$$\rightarrow a_1^{(2)} = g(\Theta_{10}^{(1)}x_0 + \Theta_{11}^{(1)}x_1 + \Theta_{12}^{(1)}x_2 + \Theta_{13}^{(1)}x_3)$$

$$\rightarrow a_2^{(2)} = g(\Theta_{20}^{(1)}x_0 + \Theta_{21}^{(1)}x_1 + \Theta_{22}^{(1)}x_2 + \Theta_{23}^{(1)}x_3)$$

$$\rightarrow a_3^{(2)} = g(\Theta_{30}^{(1)}x_0 + \Theta_{31}^{(1)}x_1 + \Theta_{32}^{(1)}x_2 + \Theta_{33}^{(1)}x_3)$$

$\Theta^{(2)}$

$$\rightarrow h_\Theta(x) = a_1^{(3)} = g(\Theta_{10}^{(2)}a_0^{(2)} + \Theta_{11}^{(2)}a_1^{(2)} + \Theta_{12}^{(2)}a_2^{(2)} + \Theta_{13}^{(2)}a_3^{(2)})$$

$\rightarrow$ If network has s_j units in layer j, s_{j+1} units in layer $j+1$, then $\Theta^{(j)}$ will be of dimension $\boxed{s_{j+1}} \times (\boxed{s_j} + 1)$.

$S_{j+1} \times (S_j + 1)$

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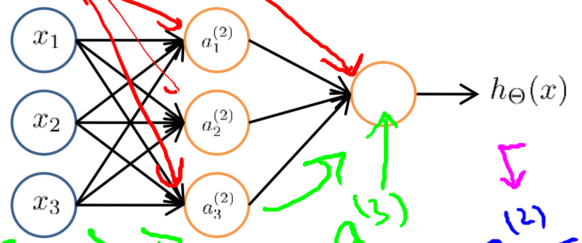
Forward propagation: Vectorized implementation



$a^{(1)} = x$

$a_1^{(3)}$

$a_1^{(2)} = g(z_1^{(2)})$

$$a_1^{(2)} = g(\underbrace{\Theta_{10}^{(1)}x_0 + \Theta_{11}^{(1)}x_1 + \Theta_{12}^{(1)}x_2 + \Theta_{13}^{(1)}x_3}_{z_1^{(2)}})$$

$$a_2^{(2)} = g(\underbrace{\Theta_{20}^{(1)}x_0 + \Theta_{21}^{(1)}x_1 + \Theta_{22}^{(1)}x_2 + \Theta_{23}^{(1)}x_3}_{z_2^{(2)}})$$

$$a_3^{(2)} = g(\underbrace{\Theta_{30}^{(1)}x_0 + \Theta_{31}^{(1)}x_1 + \Theta_{32}^{(1)}x_2 + \Theta_{33}^{(1)}x_3}_{z_3^{(2)}})$$

$$h_\Theta(x) = g(\underbrace{\Theta_{10}^{(2)}a_0^{(2)} + \Theta_{11}^{(2)}a_1^{(2)} + \Theta_{12}^{(2)}a_2^{(2)} + \Theta_{13}^{(2)}a_3^{(2)}}_{z^{(3)}})$$

$\Theta^{(1)}$ x

$a_3^{(2)} = g(z_3^{(2)})$

$$x = \begin{bmatrix} x_0 \\ x_1 \\ x_2 \\ x_3 \end{bmatrix} \qquad z^{(2)} = \begin{bmatrix} z_1^{(2)} \\ z_2^{(2)} \\ z_3^{(2)} \end{bmatrix}$$

$$z^{(2)} = \Theta^{(1)} \cancel{x}\ a^{(1)}$$

$$\boxed{a^{(2)}} = g(z^{(2)})$$

$\mathbb{R}^3$ $\quad$ $\mathbb{R}^3$

$a_1^{(2)}$, $a_2^{(2)}$, $a_3^{(2)}$

Add $a_0^{(2)} = 1$. $\longrightarrow a^{(2)} \in \mathbb{R}^4$

$$z^{(3)} = \Theta^{(2)} a^{(2)}$$

$$h_\Theta(x) = \boxed{a^{(3)}} = g(z^{(3)})$$

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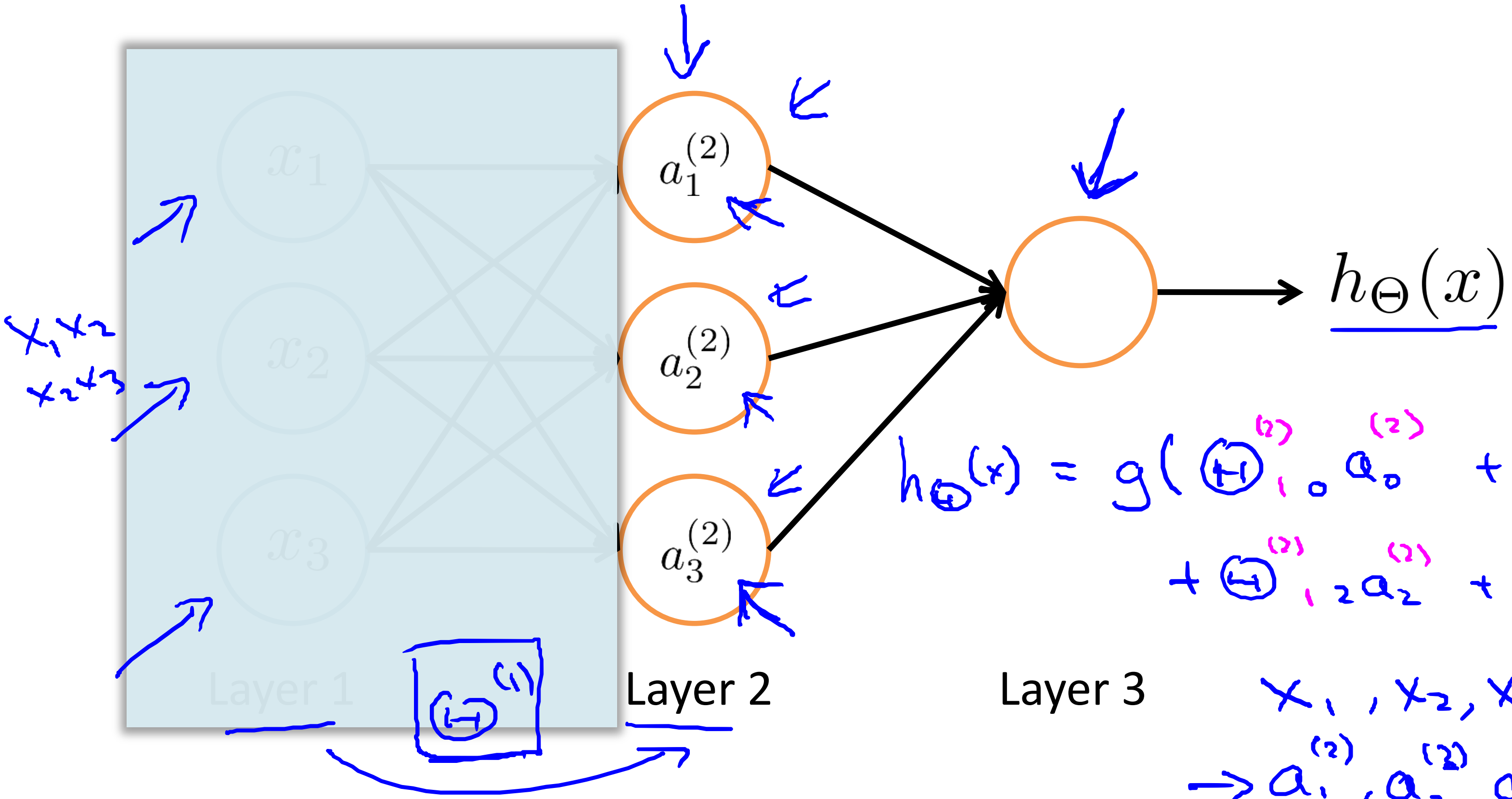
Neural Network learning its own features

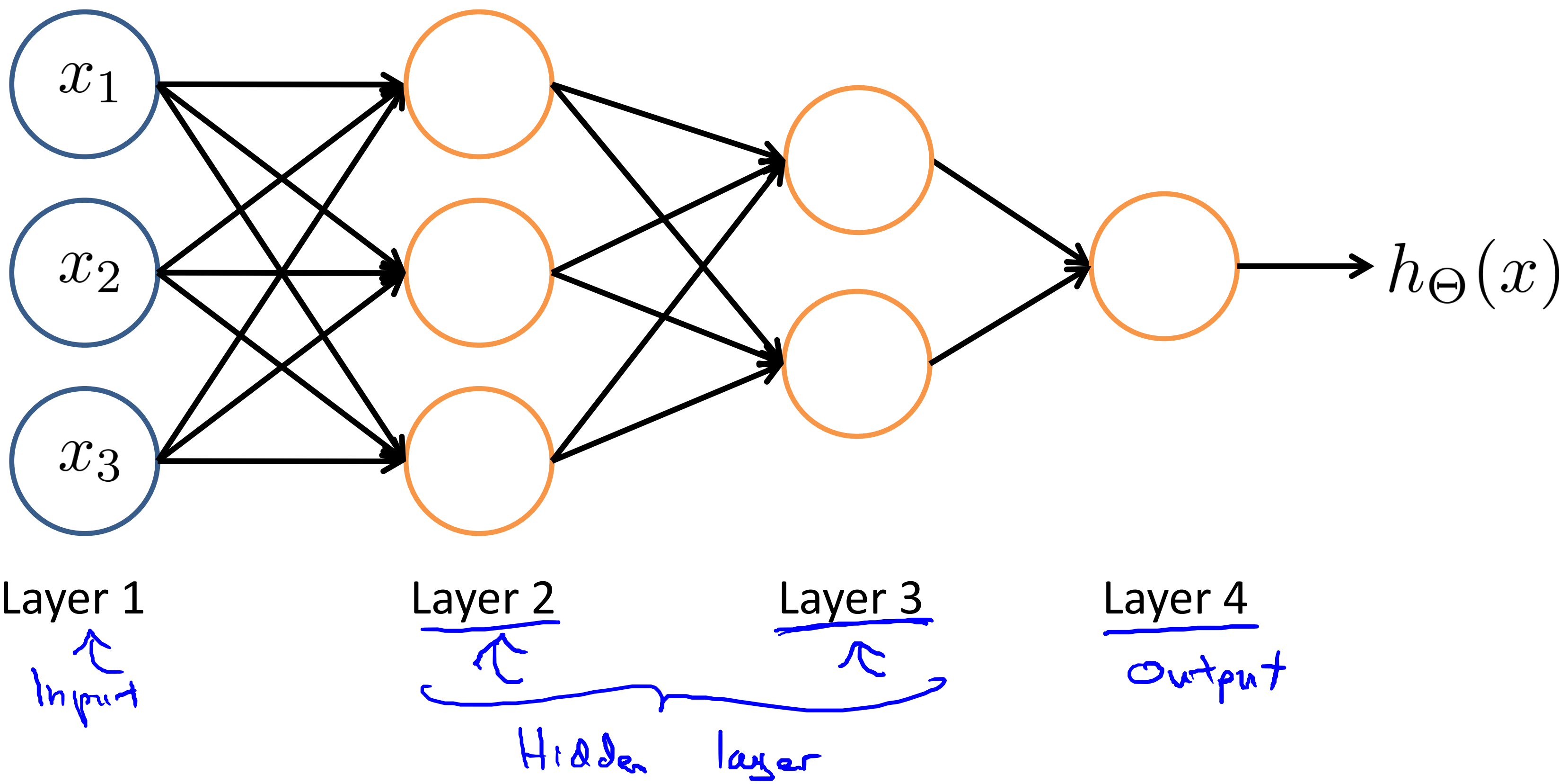


$$h_\Theta(x) = g(\Theta^{(2)}_{10} a^{(2)}_0 + \Theta^{(1)}_{11} a^{(2)}_1 + \Theta^{(2)}_{12} a^{(2)}_2 + \Theta^{(2)}_{13} a^{(2)}_3)$$

x_1, x_2, x_3

$\rightarrow a_1^{(2)}, a_2^{(2)}, a_3^{(2)}$

Other network architectures



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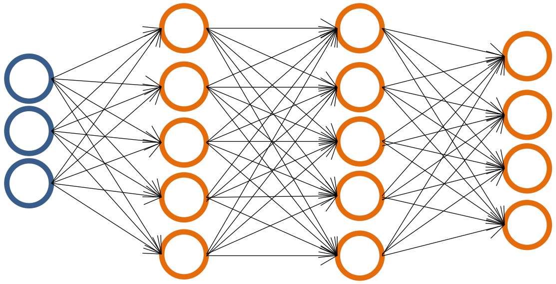
Neural Network (Classification)

$$\{(x^{(1)}, y^{(1)}), (x^{(2)}, y^{(2)}), \ldots, (x^{(m)}, y^{(m)})\}$$



$L =$ total no. of layers in network

$s_l =$ no. of units (not counting bias unit) in layer l

Binary classification

$$y = 0 \text{ or } 1$$

1 output unit

Multi-class classification (K classes)

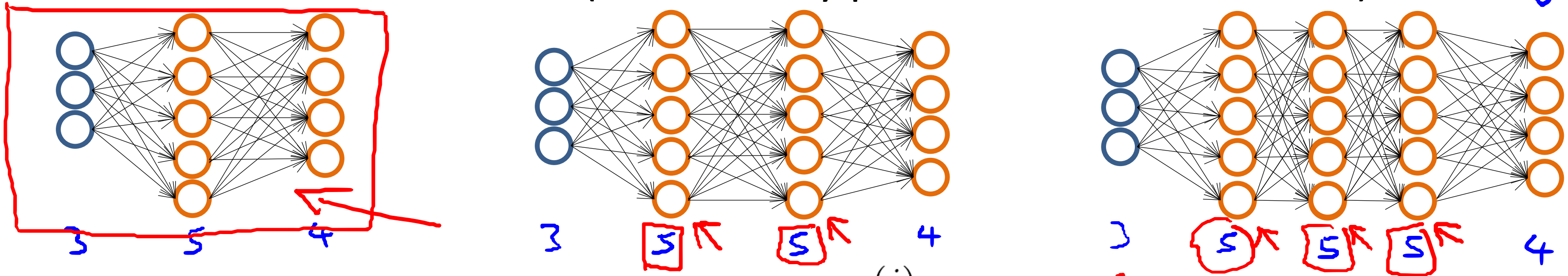
$y \in \mathbb{R}^K$ E.g. $\begin{bmatrix}1\\0\\0\\0\end{bmatrix}$, $\begin{bmatrix}0\\1\\0\\0\end{bmatrix}$, $\begin{bmatrix}0\\0\\1\\0\end{bmatrix}$, $\begin{bmatrix}0\\0\\0\\1\end{bmatrix}$

pedestrian car motorcycle truck

K output units

Training a neural network

Pick a network architecture (connectivity pattern between neurons)



- No. of input units: Dimension of features $x^{(i)}$
- No. output units: Number of classes

Reasonable default: 1 hidden layer, or if >1 hidden layer, have same no. of hidden units in every layer (usually the more the better)

$y \in \{1, 2, 3, \ldots, 10\}$

~~$y = 5$~~

$y = \begin{bmatrix} 1 \\ 0 \\ 0 \\ \vdots \\ 0 \end{bmatrix}$ or $\begin{bmatrix} 0 \\ 1 \\ 0 \\ \vdots \\ 0 \end{bmatrix}$ $\begin{bmatrix} 0 \\ 0 \\ 0 \\ 0 \\ 1 \\ 0 \\ \vdots \\ 0 \end{bmatrix}$

Training a neural network

1. Randomly initialize weights
2. Implement forward propagation to get $h_\Theta(x^{(i)})$ for any $x^{(i)}$
3. Implement code to compute cost function $J(\Theta)$
4. Implement backprop to compute partial derivatives $\boxed{\frac{\partial}{\partial \Theta^{(l)}_{jk}} J(\Theta)}$

```
for i = 1:m {
```

$(x^{(1)}, y^{(1)})$ $(x^{(2)}, y^{(2)})$, ... $(x^{(m)}, y^{(m)})$

Perform forward propagation and backpropagation using example $(x^{(i)}, y^{(i)})$

(Get activations $a^{(l)}$ and delta terms $\delta^{(l)}$ for $l = 2, \ldots, L$).

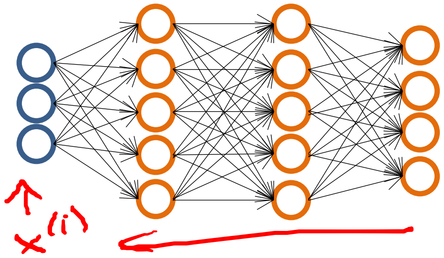
$\Delta^{(l)} := \Delta^{(l)} + \delta^{(l+1)} (a^{(l)})^T$

...

}

...

compute $\frac{\partial}{\partial \Theta^{(l)}_{jk}} J(\Theta)$.



Training a neural network

5. Use gradient checking to compare $\frac{\partial}{\partial \Theta_{jk}^{(l)}} J(\Theta)$ computed using backpropagation vs. using numerical estimate of gradient of $J(\Theta)$.

   Then disable gradient checking code.

6. Use gradient descent or advanced optimization method with backpropagation to try to minimize $J(\Theta)$ as a function of parameters Θ

$$\frac{\partial}{\partial \Theta_{jk}^{(l)}} J(\Theta)$$

$J(\Theta)$ — non-convex.