

Transfer Learning

Pranav Goel
14075039

CSE B.Tech. Pt. IV, IIT (BHU) Varanasi

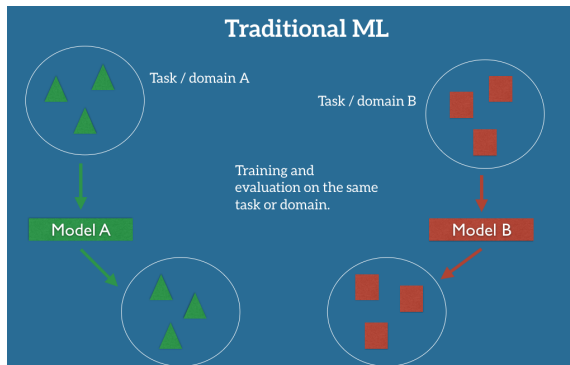
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Underlying Motivation

- We have become great at mapping inputs to outputs in the classic supervised setting.
- But we greatly lack the ability to generalize to conditions that are different from the ones encountered during training - and the real world *is* messy!
- We need the ability to transfer knowledge to new conditions - **Transfer Learning**.

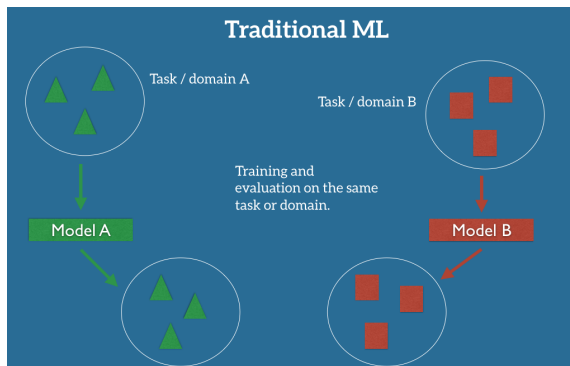
Underlying Motivation

- Classic Supervised Learning - generally assumes that the training and test set examples are from same task and domain.



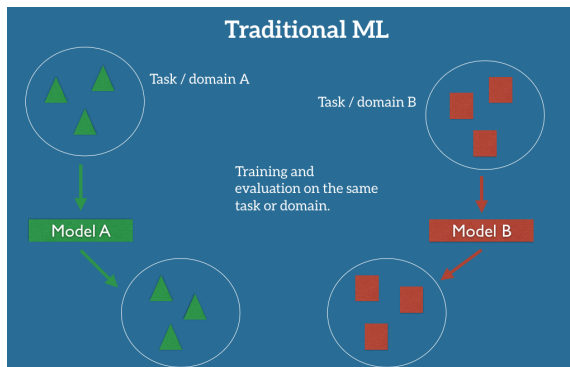
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- Task: objective of our model (like image recognition).
- Domain: where the data comes from (like images of Indian footpaths).



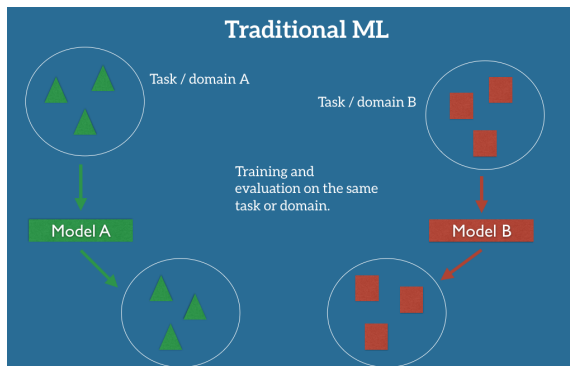
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- Traditional Supervised ML breaks down when we do NOT have *sufficient labeled data* for the task or domain we care about.



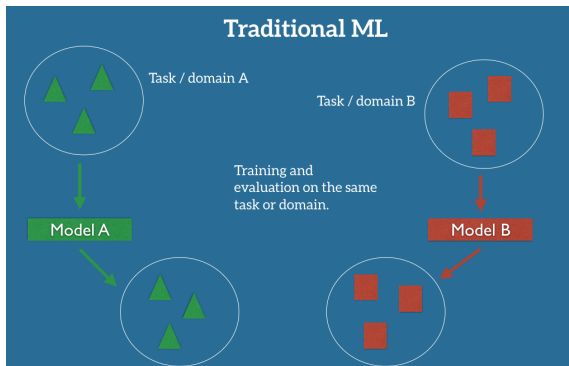
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- Traditional Supervised ML breaks down when we do NOT have **sufficient** labeled **data** for the task or **domain** we care about.
- Performance Deterioration!



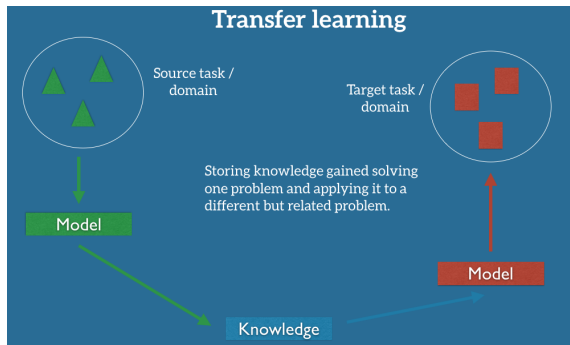
Underlying Motivation

- Traditional Supervised ML breaks down when we do NOT have sufficient **labeled data** for the **task** or domain we care about.
- Cannot reuse existing model!



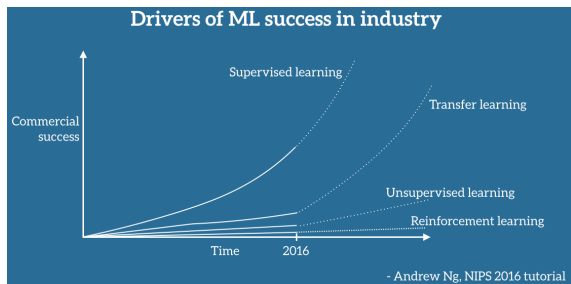
Underlying Motivation

- Transfer Learning allows us to leverage already existing labeled data of some related task or domain.



Why Transfer Learning NOW?

- “Transfer Learning will be the next driver of ML success” - Andrew Ng, NIPS 2016.



Transfer Learning *Defined*

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- So, Domain $D = \{\chi, P(X)\}$.

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- Now, the objective of transfer learning is to enable us to learn the target conditional probability distribution $P(Y_T|X_T)$ in D_T with the information gained from D_S and T_S where $D_S \neq D_T$ or $T_S \neq T_T$.

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- In most cases, we have a limited number of labeled target examples (exponentially smaller than the number of labeled source examples).

Transfer Learning *Scenarios*

- Given source and target domains D_S and D_T where $D = \{\mathcal{X}, P(X)\}$ and source and target tasks T_S and T_T where $T = \{\gamma, P(Y|X)\}$, the source and target conditions can vary in **four** ways -

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 - 3 $\gamma_S \neq \gamma_T$ (practically occurs with scenario 4).
 - 4 $P(Y_S|X_S) \neq P(Y_T|X_T)$ (imbalance with respect to the classes, usually handled with oversampling or undersampling).

Transfer Learning Methods

- Deep Learning has brought about many set of approaches for transfer learning.

Transfer Learning Methods

Using *pre-trained* CNN features

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- Mostly used in scenario 3 - adapting to new tasks.

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 - 1 A pre-processing step to get new representation to then use for training.
 - 2 Modify the learning objective or loss function.

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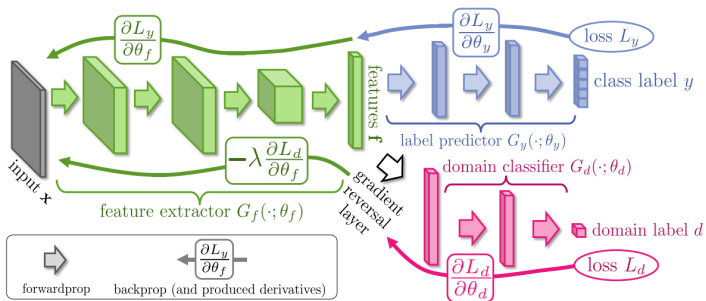
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- Difference from regular loss? Gradients that flow from the loss to the rest of the network are reversed - gradient reversal layer - causes model to try and *maximize* error.

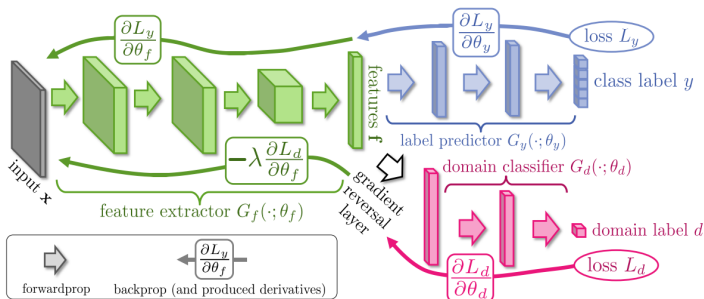
Transfer Learning Methods

Confusing Domains



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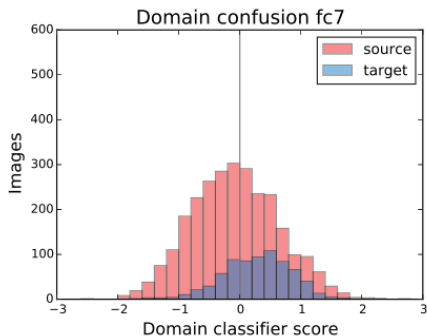
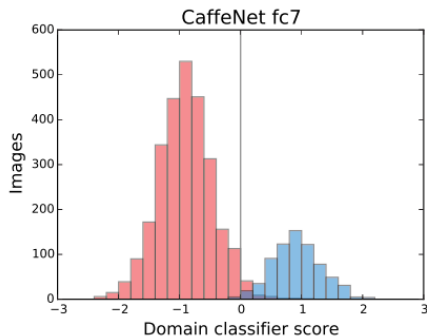
Confusing Domains



Model learns representations that allow it to **minimize** its **original objective**, while **not allowing** it to **differentiate** between the two **domains**, which is beneficial for knowledge transfer!

Transfer Learning Methods

Confusing Domains



Left - Model trained only with regular objective; learned rep. clearly separates the domains.

Right - Model objective augmented with domain confusion term.

Applications of Transfer Learning

Learning from Simulations

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- Simulation offers an alternative, less risky way to gather and use data.
- Learning from simulation, and applying the knowledge gained or making the transfer to real world - an example of scenario 2 (same feature space, different marginal probabilities).

Applications of Transfer Learning

Learning from Simulations - Benefits

- Makes data gathering easy (objects can be bounded and analyzed).

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- Enables fast training (learning can be parallelized across multiple instances).

Applications of Transfer Learning

Learning from Simulations - Self-Driving Cars

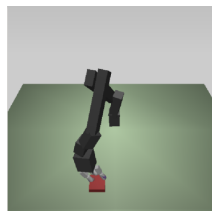
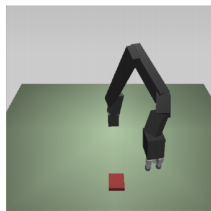
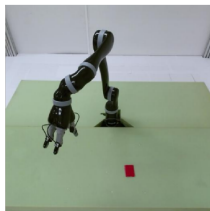


Udacity's self-driving car simulator

Applications of Transfer Learning

Learning from Simulations - Robotics

Training models on a real robot is too slow and robots are expensive to train.



Robot and simulation images

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Adapting to New Domains

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Adapting to New Domains

- Data where labeled information is easily accessible and the data that we actually care about are often different.
- Even if training and test sets *look* the same, training data may contain some bias (which we cannot perceive) that will be exploited by model to overfit.

Applications of Transfer Learning

Adapting to New Domains

Domain 1



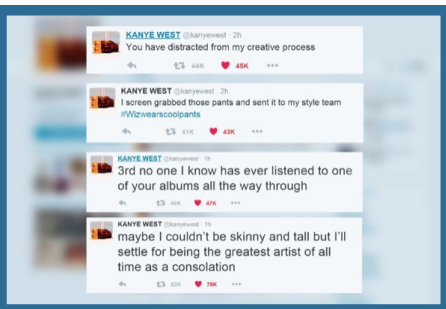
Domain 2



Different visual domains

Applications of Transfer Learning

Adapting to New Domains



Different text types/genres

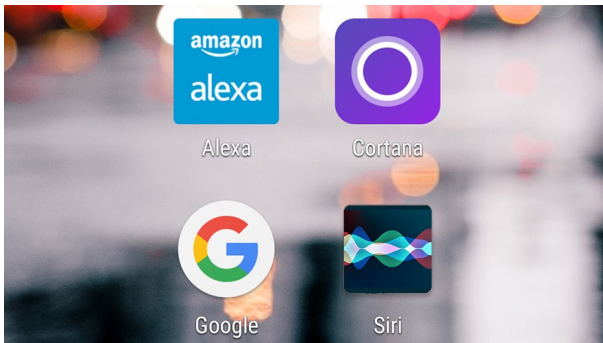
Applications of Transfer Learning

Next level challenge - domains pertaining to *individual* or *groups of users*

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Consider **Automatic Speech Recognition (ASR)**



Thank You

Questions?