

Conditional Random Fields and beyond ...



DANIEL KHASHABI

CS 546

UIUC, 2013

Outline



- Modeling
- Inference
- Training
- Applications

Outline



- **Modeling**
 - Problem definition
 - Discriminative vs. Generative
 - Chain CRF
 - General CRF
- Inference
- Training
- Applications

Problem Description

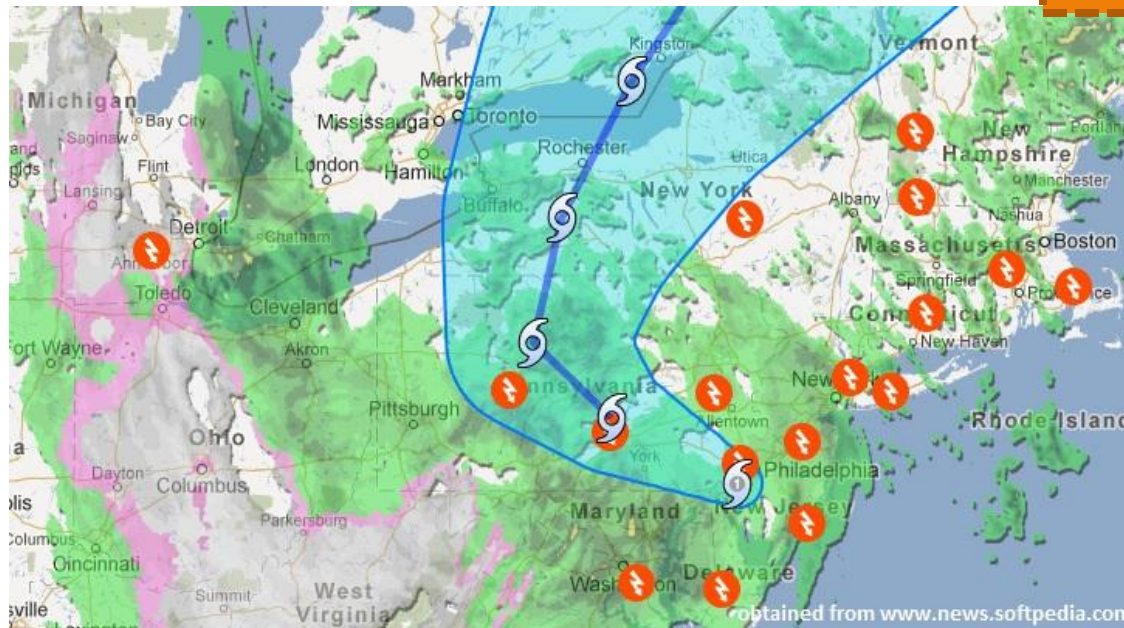


- Given X (observations), find Y (predictions)
- For example,

$$\begin{cases} X = \{temperature, moisture, pressure, \dots\} \\ Y = \{Sunny, Rainy, Stormy, \dots\} \end{cases}$$

Might depend on previous days and each other

Might depend on previous days and each other



Problem Description



- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,


Problem Description



- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models,


Problem Description



- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models,  $p(\mathbf{x}, \mathbf{y})$


Problem Description



- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models,  $p(\mathbf{x}, \mathbf{y}) = p(\mathbf{y} | \mathbf{x}) p(\mathbf{x})$


Problem Description



- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models,  $p(\mathbf{x}, \mathbf{y}) = p(\mathbf{y} | \mathbf{x})p(\mathbf{x})$
 - Modeling the joint distribution can lead to difficulties




Problem Description



- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models,  $p(\mathbf{x}, \mathbf{y}) = p(\mathbf{y} | \mathbf{x})p(\mathbf{x})$
 - Modeling the joint distribution can lead to difficulties
 - rich local features occur in relational data,

Problem Description

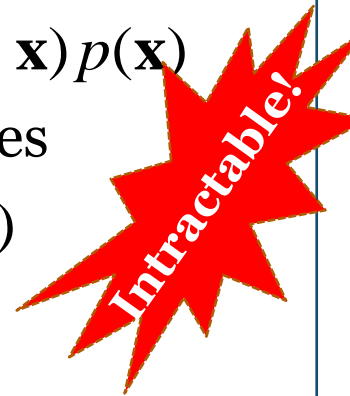


- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
 - Traditionally in graphical models,  $p(\mathbf{x}, \mathbf{y}) = p(\mathbf{y} | \mathbf{x})p(\mathbf{x})$
 - Modeling the joint distribution can lead to difficulties
 - rich local features occur in relational data,  $p(\mathbf{x})$
- 

Problem Description



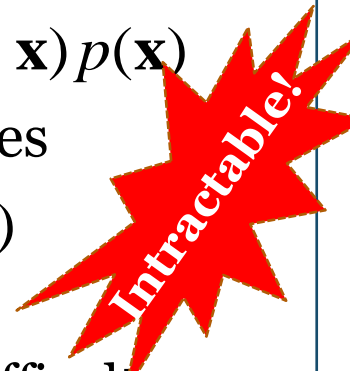
- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models, $\longrightarrow p(\mathbf{x}, \mathbf{y}) = p(\mathbf{y} | \mathbf{x}) p(\mathbf{x})$
 - Modeling the joint distribution can lead to difficulties
 - rich local features occur in relational data, $\longrightarrow p(\mathbf{x})$



Problem Description



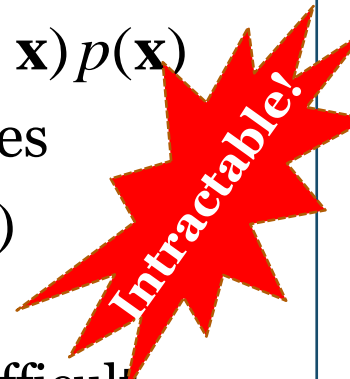
- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models, $\longrightarrow p(\mathbf{x}, \mathbf{y}) = p(\mathbf{y} | \mathbf{x}) p(\mathbf{x})$
 - Modeling the joint distribution can lead to difficulties
 - rich local features occur in relational data, $\longrightarrow p(\mathbf{x})$
 - features may have complex dependencies,
 - constructing probability distribution over them is difficult



Problem Description



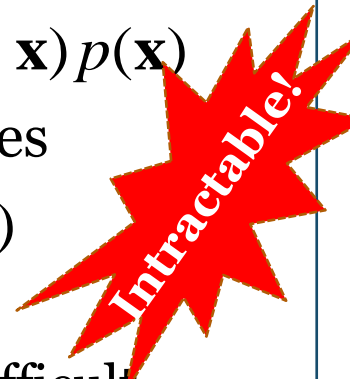
- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models, $\longrightarrow p(\mathbf{x}, \mathbf{y}) = p(\mathbf{y} | \mathbf{x}) p(\mathbf{x})$
 - Modeling the joint distribution can lead to difficulties
 - rich local features occur in relational data, $\longrightarrow p(\mathbf{x})$
 - features may have complex dependencies,
 - constructing probability distribution over them is difficult
- **Solution:** directly model the conditional, $p(\mathbf{y} | \mathbf{x})$
 - is sufficient for classification!



Problem Description



- The relational connection occurs in many applications, NLP, Computer Vision, Signal Processing,
- Traditionally in graphical models, $\longrightarrow p(\mathbf{x}, \mathbf{y}) = p(\mathbf{y} | \mathbf{x}) p(\mathbf{x})$
 - Modeling the joint distribution can lead to difficulties
 - rich local features occur in relational data, $\longrightarrow p(\mathbf{x})$
 - features may have complex dependencies,
 - constructing probability distribution over them is difficult
- **Solution:** directly model the conditional, $p(\mathbf{y} | \mathbf{x})$
 - is sufficient for classification!
- **CRF** is simply a **conditional distribution** $p(\mathbf{y} | \mathbf{x})$ with an **associated graphical structure**



Discriminative Vs. Generative



$p(\mathbf{y}, \mathbf{x})$

$p(\mathbf{y} | \mathbf{x})$

Discriminative Vs. Generative



- **Generative Model:** A model that generate observed data randomly

$$p(\mathbf{y}, \mathbf{x})$$

$$p(\mathbf{y} | \mathbf{x})$$

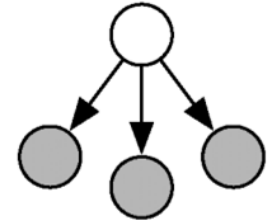
Discriminative Vs. Generative



$p(\mathbf{y}, \mathbf{x})$

- **Generative Model:** A model that generate observed data randomly
- **Naïve Bayes:** once the class label is known, all the features are independent

$$p(y, \mathbf{x}) = p(y) \prod_{k=1}^K p(x_k | y)$$



Naive Bayes

$p(\mathbf{y} | \mathbf{x})$

Discriminative Vs. Generative



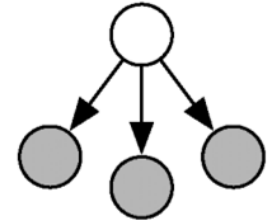
$$p(\mathbf{y}, \mathbf{x})$$

- **Generative Model:** A model that generate observed data randomly
- **Naïve Bayes:** once the class label is known, all the features are independent

$$p(y, \mathbf{x}) = p(y) \prod_{k=1}^K p(x_k | y)$$

- **Discriminative:** Directly estimate the posterior probability; Aim at modeling the “discrimination” between different outputs

$$p(\mathbf{y} | \mathbf{x})$$



Naive Bayes

Discriminative Vs. Generative



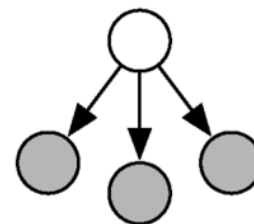
$$p(\mathbf{y}, \mathbf{x})$$

- **Generative Model:** A model that generate observed data randomly
- **Naïve Bayes:** once the class label is known, all the features are independent

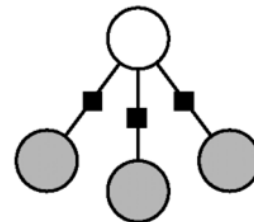
$$p(y, \mathbf{x}) = p(y) \prod_{k=1}^K p(x_k | y)$$

- **Discriminative:** Directly estimate the posterior probability; Aim at modeling the “discrimination” between different outputs

$$p(\mathbf{y} | \mathbf{x})$$



Naive Bayes



Logistic Regression

Discriminative Vs. Generative



$p(\mathbf{y}, \mathbf{x})$

- **Generative Model:** A model that generate observed data randomly
- **Naïve Bayes:** once the class label is known, all the features are independent

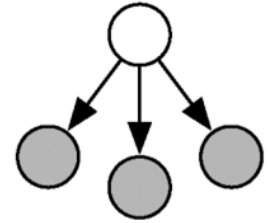
$$p(y, \mathbf{x}) = p(y) \prod_{k=1}^K p(x_k | y)$$

- **Discriminative:** Directly estimate the posterior probability; Aim at modeling the “discrimination” between different outputs

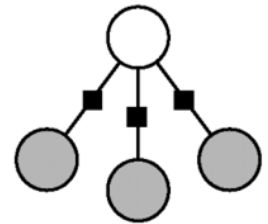
$p(\mathbf{y} | \mathbf{x})$

- **MaxEnt classifier:** linear combination of feature function in the exponent,

$$p(y|\mathbf{x}) = \frac{1}{Z(\mathbf{x})} \exp \left\{ \sum_{k=1}^K \theta_k f_k(y, \mathbf{x}) \right\}$$



Naive Bayes



Logistic Regression

Discriminative Vs. Generative



$p(\mathbf{y}, \mathbf{x})$

- **Generative Model:** A model that generate observed data randomly
- **Naïve Bayes:** once the class label is known, all the features are independent

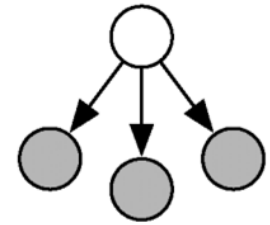
$$p(y, \mathbf{x}) = p(y) \prod_{k=1}^K p(x_k | y)$$

- **Discriminative:** Directly estimate the posterior probability; Aim at modeling the “discrimination” between different outputs

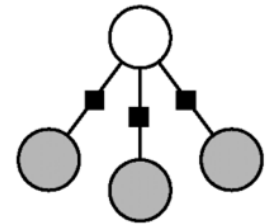
$p(\mathbf{y} | \mathbf{x})$

- **MaxEnt classifier:** linear combination of feature function in the exponent,

$$p(y|\mathbf{x}) = \frac{1}{Z(\mathbf{x})} \exp \left\{ \sum_{k=1}^K \theta_k f_k(y, \mathbf{x}) \right\}$$



Naive Bayes



Logistic Regression

Both generative models and discriminative models describe distributions over (y, \mathbf{x}) , but they work in different directions.

Discriminative Vs. Generative



$$p(\mathbf{y}, \mathbf{x})$$

$$p(\mathbf{y} | \mathbf{x})$$

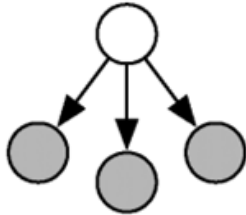
○=observable

○=unobservable

Discriminative Vs. Generative



$p(\mathbf{y}, \mathbf{x})$



Naive Bayes

$p(\mathbf{y} | \mathbf{x})$

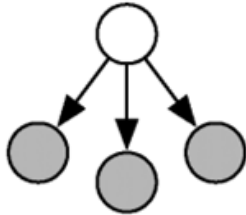
○=observable

○=unobservable

Discriminative Vs. Generative



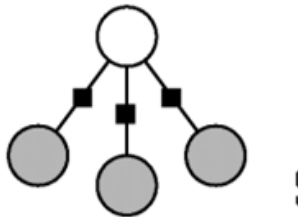
$p(\mathbf{y}, \mathbf{x})$



Naive Bayes

CONDITIONAL

$p(\mathbf{y} | \mathbf{x})$



ogistic Regression

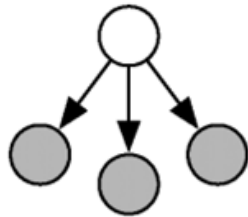
○=observable

○=unobservable

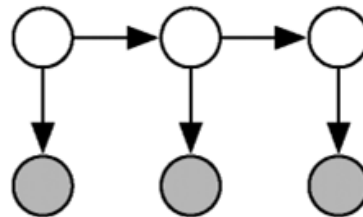
Discriminative Vs. Generative



$p(\mathbf{y}, \mathbf{x})$



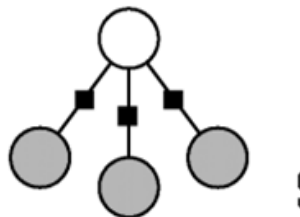
Naive Bayes



HMMs



$p(\mathbf{y} | \mathbf{x})$



ogistic Regression

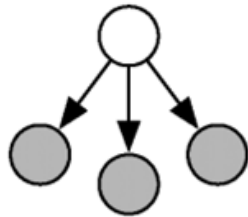
○=observable

○=unobservable

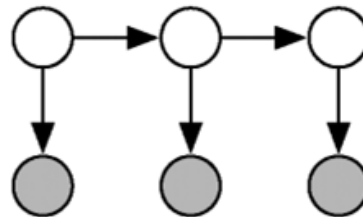
Discriminative Vs. Generative



$p(\mathbf{y}, \mathbf{x})$



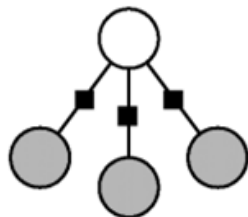
Naive Bayes



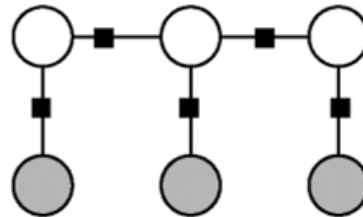
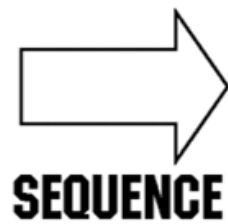
HMMs



$p(\mathbf{y} | \mathbf{x})$



logistic Regression



Linear-chain CRFs

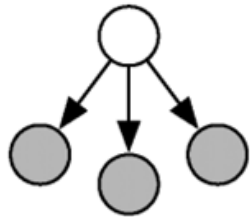
○=observable

○=unobservable

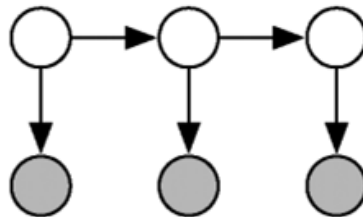
Discriminative Vs. Generative



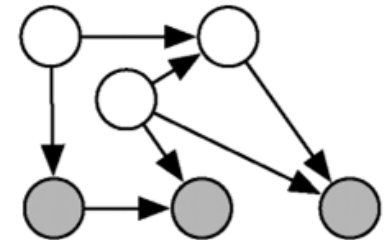
$p(\mathbf{y}, \mathbf{x})$



Naive Bayes



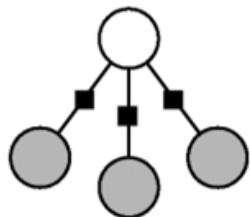
HMMs



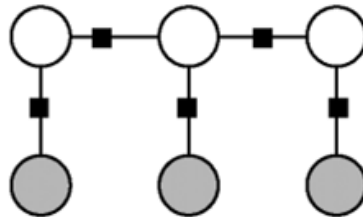
Generative directed model:



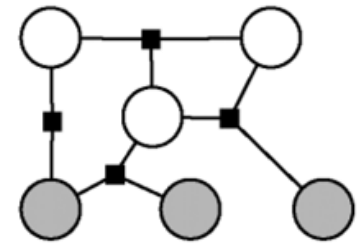
$p(\mathbf{y} | \mathbf{x})$



Logistic Regression



Linear-chain CRFs



General CRFs

○=observable

○=unobservable

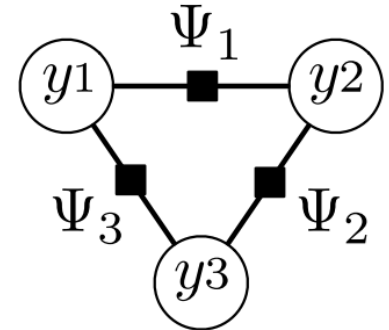
Markov Random Field(MRF) and Factor Graphs



- On an **undirected** graph, the **joint** distribution of variables \mathbf{y}

$$p(\mathbf{y}) = \frac{1}{Z} \prod_C \psi_C(\mathbf{y}_C), \quad Z = \sum_{\mathbf{y}} \prod_C \psi_C(\mathbf{y}_C)$$

- $\psi_C(\mathbf{y}_C) \geq 0$: Potential function
- Typically : $\psi_C(\mathbf{y}_C) = \exp\{-E(\mathbf{y}_C)\}$
- Z : Partition function



Markov Random Field(MRF) and Factor Graphs

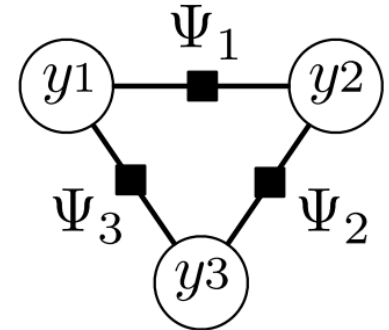


- On an **undirected** graph, the **joint** distribution of variables \mathbf{y}

$$p(\mathbf{y}) = \frac{1}{Z} \prod_C \psi_C(\mathbf{y}_C), \quad Z = \sum_{\mathbf{y}} \prod_C \psi_C(\mathbf{y}_C)$$

- $\psi_C(\mathbf{y}_C) \geq 0$: Potential function
- Typically : $\psi_C(\mathbf{y}_C) = \exp\{-E(\mathbf{y}_C)\}$
- Z : Partition function

$$p(y_1, y_2, y_3) \propto \Psi_1(y_1, y_2) \Psi_2(y_2, y_3) \Psi_3(y_1, y_3)$$



Markov Random Field(MRF) and Factor Graphs

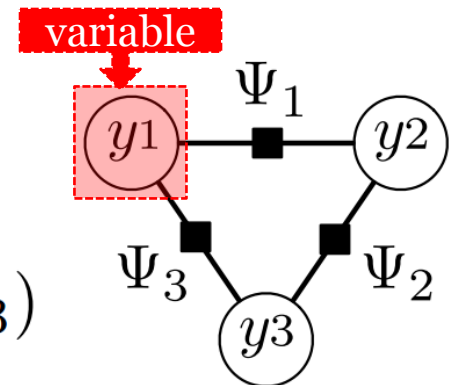


- On an **undirected** graph, the **joint** distribution of variables \mathbf{y}

$$p(\mathbf{y}) = \frac{1}{Z} \prod_C \psi_C(\mathbf{y}_C), \quad Z = \sum_{\mathbf{y}} \prod_C \psi_C(\mathbf{y}_C)$$

- $\psi_C(\mathbf{y}_C) \geq 0$: Potential function
- Typically : $\psi_C(\mathbf{y}_C) = \exp\{-E(\mathbf{y}_C)\}$
- Z : Partition function

$$p(y_1, y_2, y_3) \propto \Psi_1(y_1, y_2) \Psi_2(y_2, y_3) \Psi_3(y_1, y_3)$$



Markov Random Field(MRF) and Factor Graphs

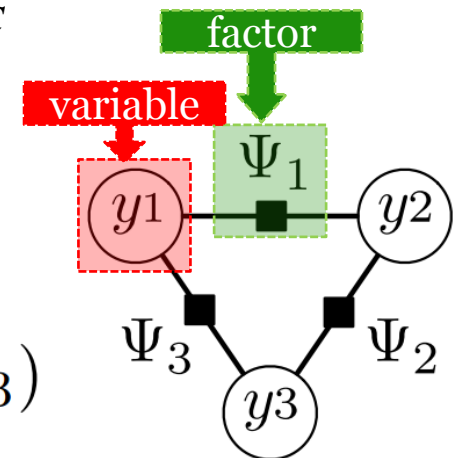


- On an **undirected** graph, the **joint** distribution of variables \mathbf{y}

$$p(\mathbf{y}) = \frac{1}{Z} \prod_C \psi_C(\mathbf{y}_C), \quad Z = \sum_{\mathbf{y}} \prod_C \psi_C(\mathbf{y}_C)$$

- $\psi_C(\mathbf{y}_C) \geq 0$: Potential function
- Typically : $\psi_C(\mathbf{y}_C) = \exp\{-E(\mathbf{y}_C)\}$
- Z : Partition function

$$p(y_1, y_2, y_3) \propto \Psi_1(y_1, y_2) \Psi_2(y_2, y_3) \Psi_3(y_1, y_3)$$



Markov Random Field(MRF) and Factor Graphs

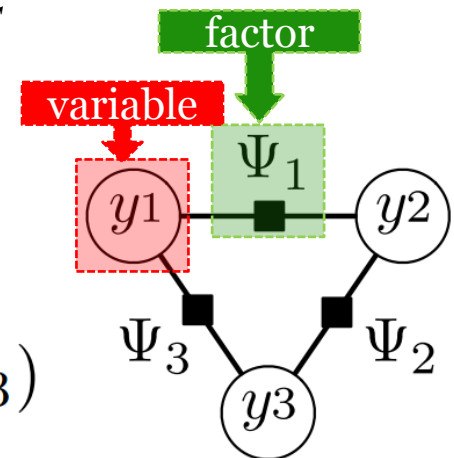


- On an **undirected** graph, the **joint** distribution of variables \mathbf{y}

$$p(\mathbf{y}) = \frac{1}{Z} \prod_C \psi_C(\mathbf{y}_C), \quad Z = \sum_{\mathbf{y}} \prod_C \psi_C(\mathbf{y}_C)$$

- $\psi_C(\mathbf{y}_C) \geq 0$: Potential function
- Typically : $\psi_C(\mathbf{y}_C) = \exp\{-E(\mathbf{y}_C)\}$
- Z : Partition function

$$p(y_1, y_2, y_3) \propto \Psi_1(y_1, y_2) \Psi_2(y_2, y_3) \Psi_3(y_1, y_3)$$



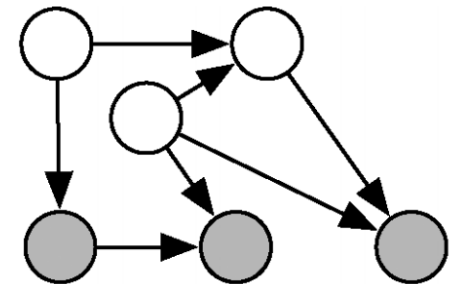
- Not all distributions satisfy Markovian properties
 - Hammersley-Clifford Theorem
 - The ones which do can be factorized

Directed Graphical Models (Bayesian Network)



- Local conditional distributions
 - If $\pi(s)$ indices of the parents of y_s

$$p(\mathbf{y}) = \prod_{s=1}^S p(y_s | \mathbf{y}_{\pi(s)}).$$

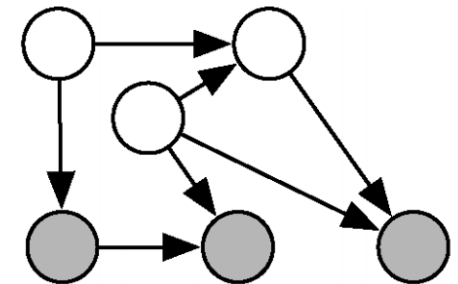


Directed Graphical Models (Bayesian Network)



- Local conditional distributions
 - If $\pi(s)$ indices of the parents of y_s

$$p(\mathbf{y}) = \prod_{s=1}^S p(y_s | \mathbf{y}_{\pi(s)}).$$



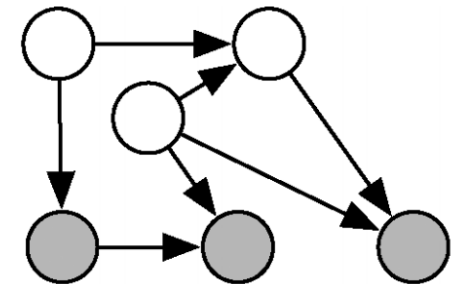
- Generally used as generative models
 - E.g. **Naïve Bayes**: once the class label is known, all the features are independent

Directed Graphical Models (Bayesian Network)



- Local conditional distributions
 - If $\pi(s)$ indices of the parents of y_s

$$p(\mathbf{y}) = \prod_{s=1}^S p(y_s | \mathbf{y}_{\pi(s)}).$$



- Generally used as generative models
 - E.g. **Naïve Bayes**: once the class label is known, all the features are independent

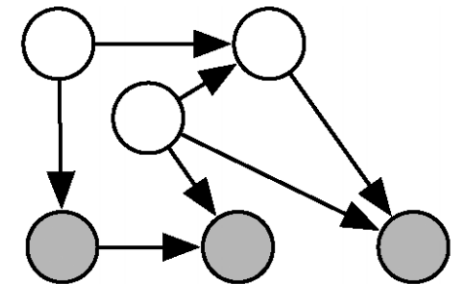
$$p(y, \mathbf{x}) = p(y) \prod_{k=1}^K p(x_k | y)$$

Directed Graphical Models (Bayesian Network)



- Local conditional distributions
 - If $\pi(s)$ indices of the parents of y_s

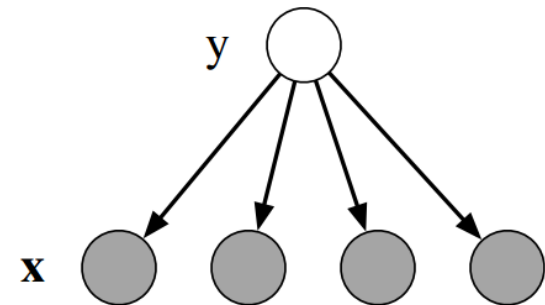
$$p(\mathbf{y}) = \prod_{s=1}^S p(y_s | \mathbf{y}_{\pi(s)}).$$



- Generally used as generative models

- E.g. **Naïve Bayes**: once the class label is known, all the features are independent

$$p(\mathbf{y}, \mathbf{x}) = p(y) \prod_{k=1}^K p(x_k | y)$$



Sequence prediction



- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations
 - Set of **observation**,

Sequence prediction



- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations
 - Set of **observation**,


$$X = \{x_t\}_{t=1}^T$$

Sequence prediction





- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations
 - Set of **observation**,
 - Set of **underlying sequence of states**,


$$X = \{x_t\}_{t=1}^T$$

Sequence prediction



- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations
 - Set of **observation**,  $X = \{x_t\}_{t=1}^T$
 - Set of **underlying sequence of states**,  $Y = \{y_t\}_{t=1}^T$

Sequence prediction




- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations

- Set of **observation**,

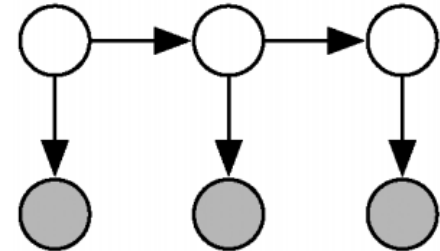

$$X = \{x_t\}_{t=1}^T$$

- Set of **underlying sequence of states**,


$$Y = \{y_t\}_{t=1}^T$$

- HMM is generative:

$$p(\mathbf{y}, \mathbf{x}) = \prod_{t=1}^T p(y_t | y_{t-1}) p(x_t | y_t)$$

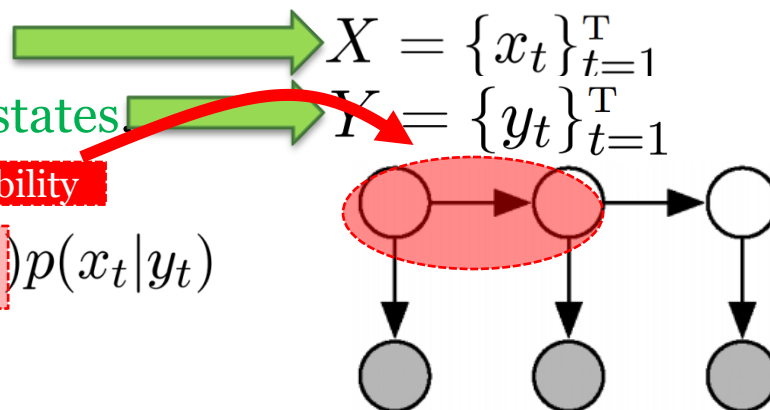


Sequence prediction



- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations
 - Set of **observation**,
 - Set of **underlying sequence of states**.
- HMM is generative:

$$p(\mathbf{y}, \mathbf{x}) = \prod_{t=1} p(y_t | y_{t-1}) p(x_t | y_t)$$



Sequence prediction



- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations

- Set of **observation**,

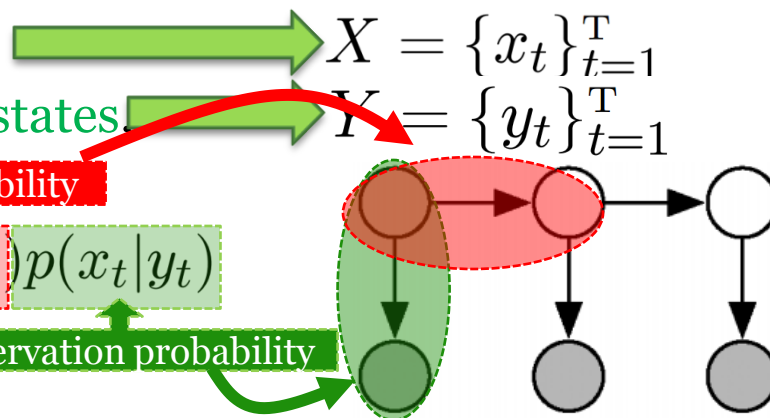
- Set of **underlying sequence of states**.

- HMM is generative:

$$p(\mathbf{y}, \mathbf{x}) = \prod_{t=1} p(y_t | y_{t-1}) p(x_t | y_t)$$

Transition probability

Observation probability



Sequence prediction



- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations

- Set of **observation**,

- Set of **underlying sequence of states**.

$$X = \{x_t\}_{t=1}^T$$

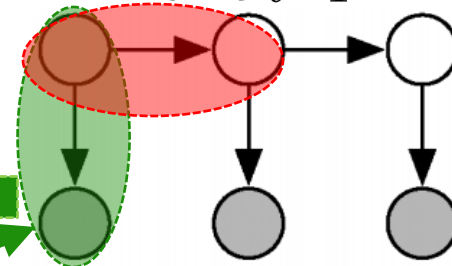
$$Y = \{y_t\}_{t=1}^T$$

- HMM is generative:

$$p(\mathbf{y}, \mathbf{x}) = \prod_{t=1}^T p(y_t | y_{t-1}) p(x_t | y_t)$$

Transition probability

Observation probability



- Doesn't model long-range dependencies
- Not practical to represent multiple interacting features (hard to model $p(\mathbf{x})$)

Sequence prediction



- Like NER: identifying and classifying proper names in text, e.g. China as location; George Bush as people; United Nations as organizations

- Set of **observation**,

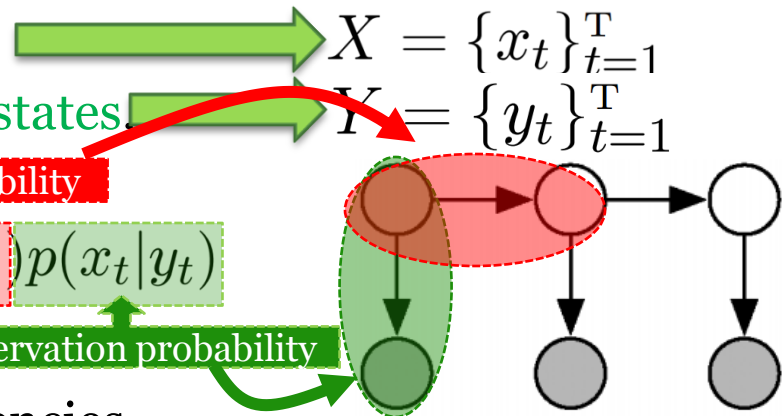
- Set of **underlying sequence of states**.

- HMM is generative:

$$p(\mathbf{y}, \mathbf{x}) = \prod_{t=1} p(y_t | y_{t-1}) p(x_t | y_t)$$

Transition probability

Observation probability



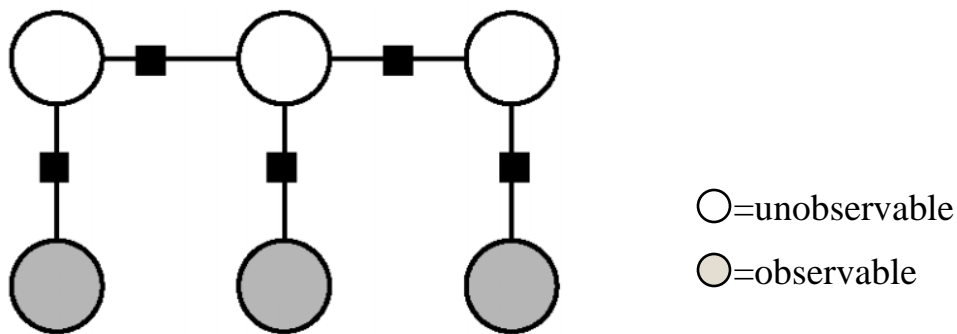
- Doesn't model long-range dependencies
- Not practical to represent multiple interacting features (hard to model $p(\mathbf{x})$)
- The primary advantage of CRFs over hidden Markov models is their conditional nature, resulting in the relaxation of the independence assumption
- And it can handle overlapping features

Chain CRFs



- Each potential function will operate on pairs of adjacent label variables

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp\left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x})\right)$$



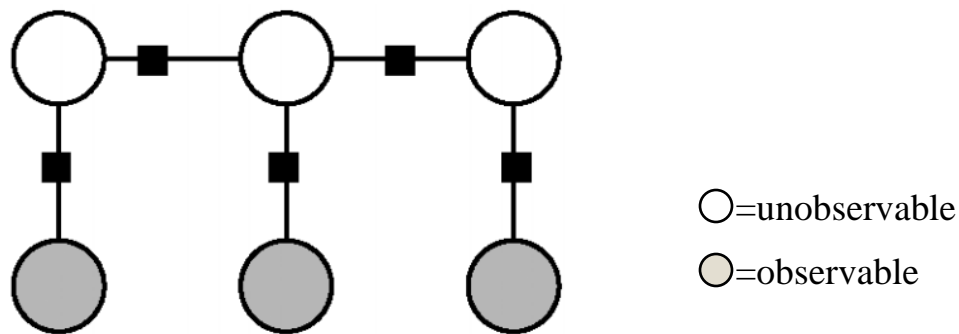
Chain CRFs



- Each potential function will operate on pairs of adjacent label variables

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp\left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x})\right)$$

$$F_j(\mathbf{y}, \mathbf{x}) = \sum_{i=1} f_j(y_{i-1}, y_i, \mathbf{x}, i),$$



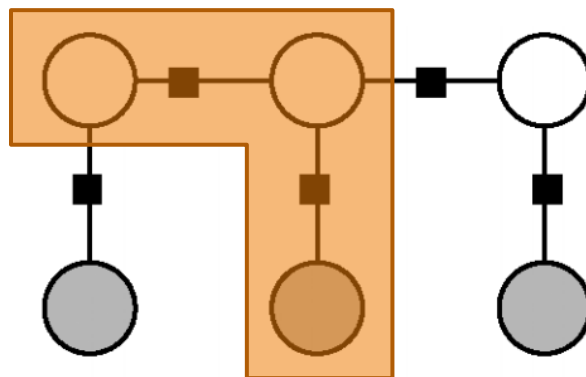
Chain CRFs



- Each potential function will operate on pairs of adjacent label variables

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp\left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x})\right)$$

$$F_j(\mathbf{y}, \mathbf{x}) = \sum_{i=1} f_j(y_{i-1}, y_i, \mathbf{x}, i), \quad \text{Feature functions}$$



○=unobservable

●=observable

Chain CRFs

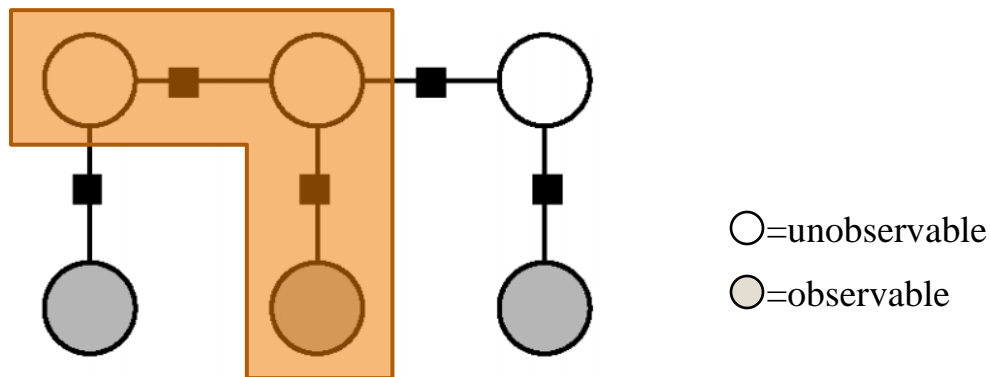


- Each potential function will operate on pairs of adjacent label variables

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp\left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x})\right)$$

$$F_j(\mathbf{y}, \mathbf{x}) = \sum_{i=1} f_j(y_{i-1}, y_i, \mathbf{x}, i), \quad \text{Feature functions}$$

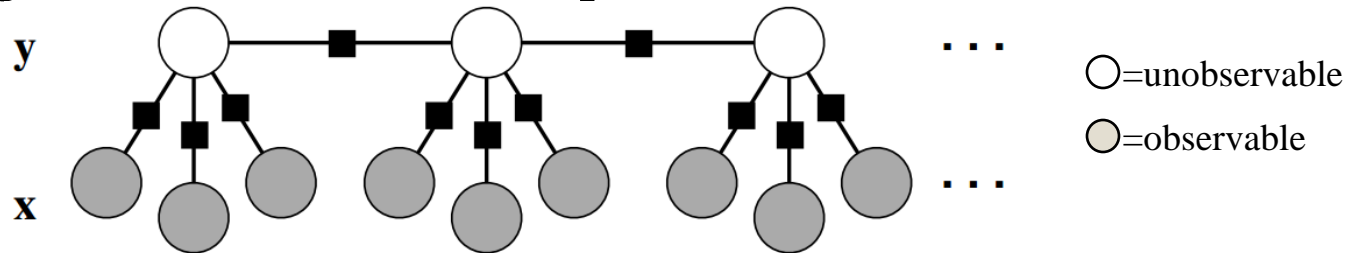
- Parameters to be estimated, λ_j



Chain CRF



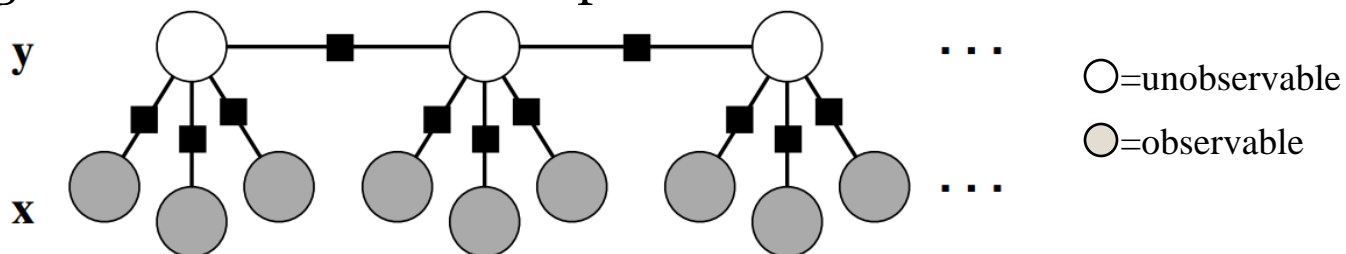
- We can change it so that each state depends on more observations



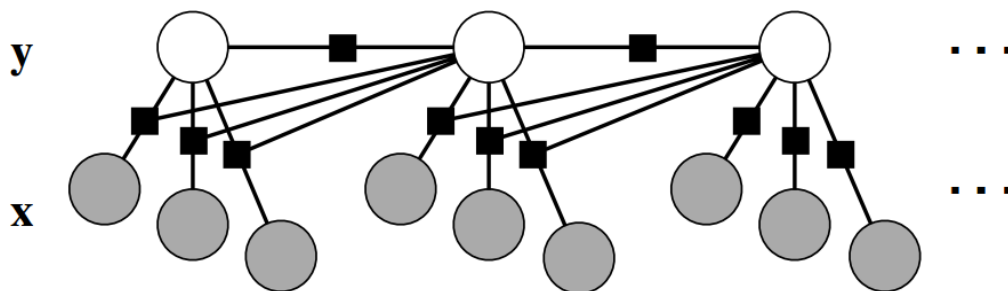
Chain CRF



- We can change it so that each state depends on more observations



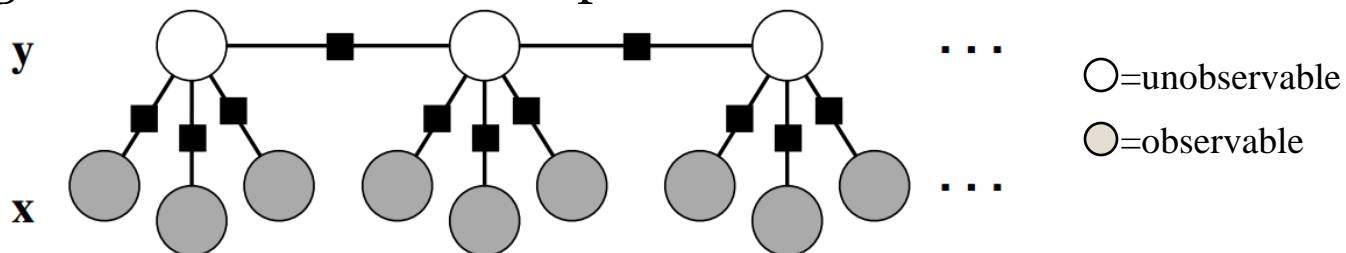
- Or inputs at previous steps



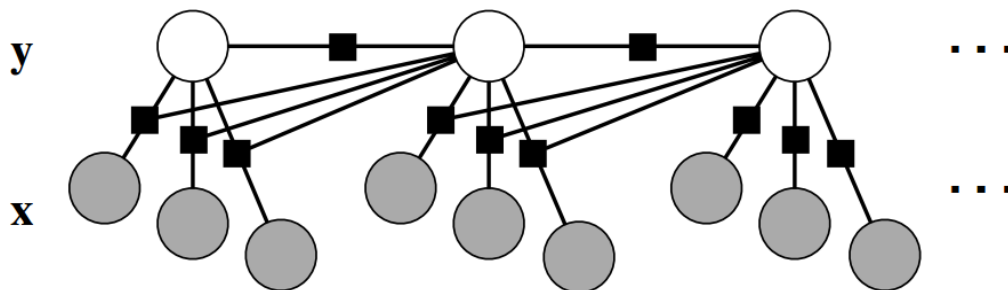
Chain CRF



- We can change it so that each state depends on more observations



- Or inputs at previous steps

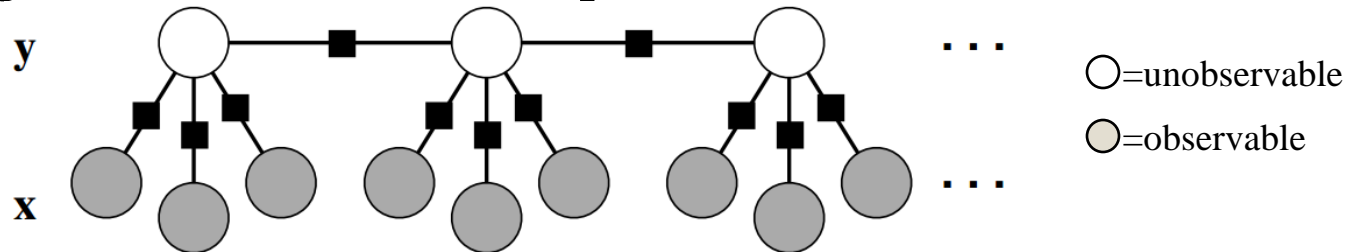


- Or all inputs

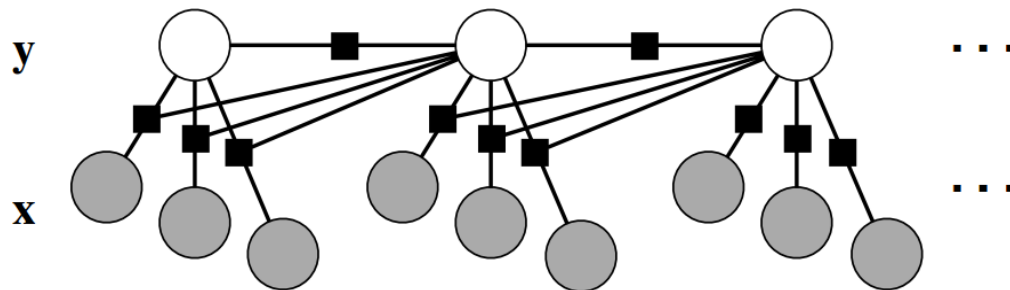
Chain CRF



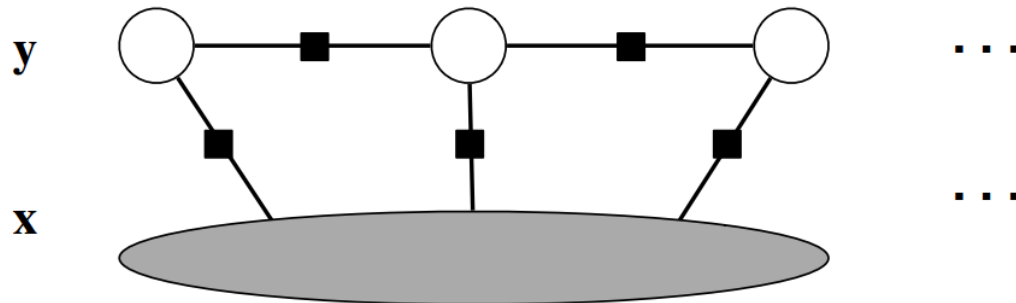
- We can change it so that each state depends on more observations



- Or inputs at previous steps



- Or all inputs

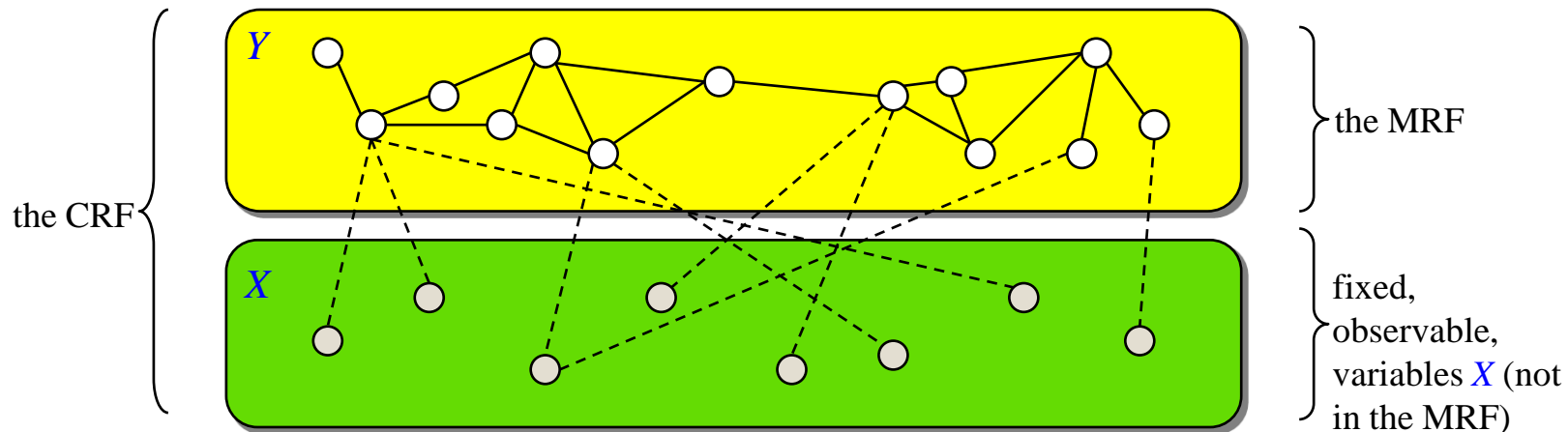


General CRF: visualization



- If $G = (V, E)$, and $\mathbf{Y} = (\mathbf{Y}_v)_{v \in V}$;
 $w \sim v \iff w$ and v are neighbors

(\mathbf{X}, \mathbf{Y}) is a CRF, if $p(\mathbf{Y}_v | \mathbf{X}, \mathbf{Y}_w, w \neq v) = p(\mathbf{Y}_v | \mathbf{X}, \mathbf{Y}_w, w \sim v)$.

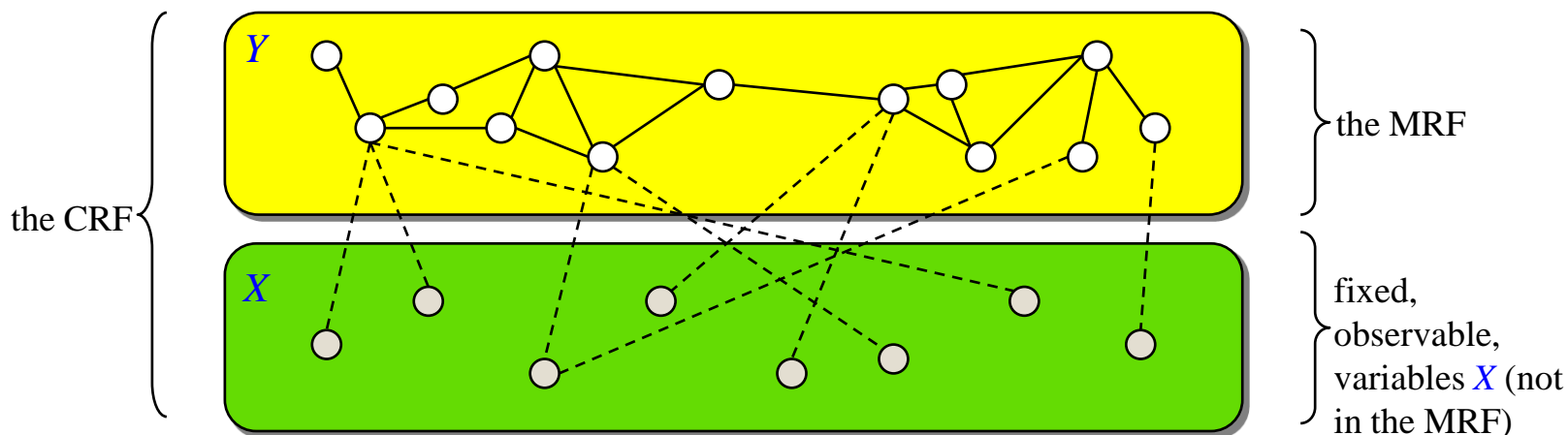


General CRF: visualization



- If $G = (V, E)$, and $\mathbf{Y} = (\mathbf{Y}_v)_{v \in V}$;
 $w \sim v \iff w$ and v are neighbors

(\mathbf{X}, \mathbf{Y}) is a CRF, if $p(\mathbf{Y}_v | \mathbf{X}, \mathbf{Y}_w, w \neq v) = p(\mathbf{Y}_v | \mathbf{X}, \mathbf{Y}_w, w \sim v)$.



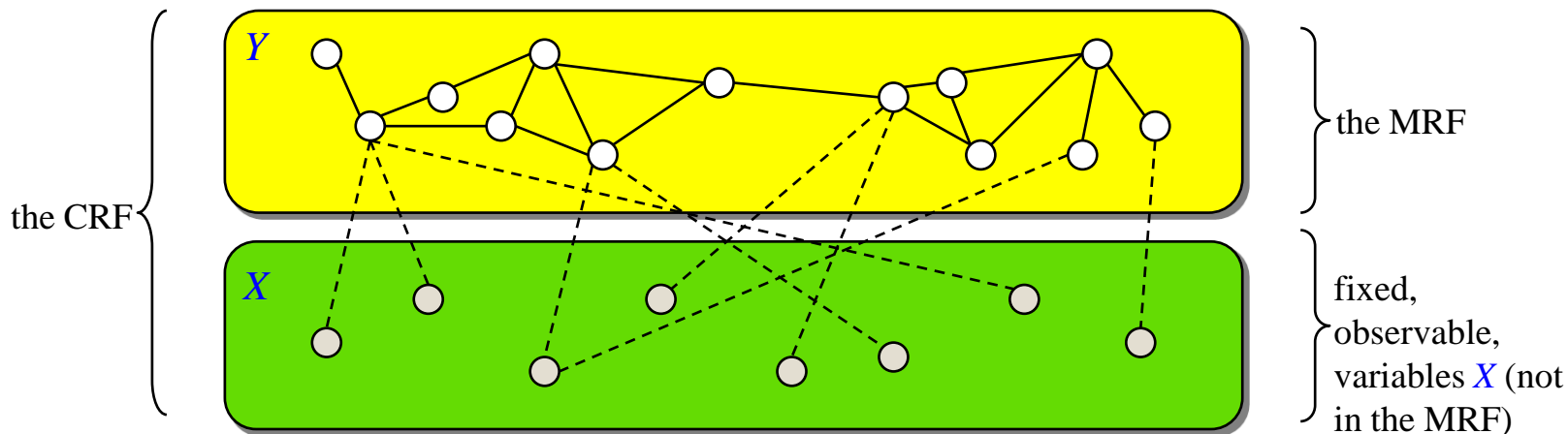
Note that in a CRF *we do not explicitly model any direct relationships between the observables (i.e., among the X)* (Lafferty *et al.*, 2001).

General CRF: visualization



- If $G = (V, E)$, and $\mathbf{Y} = (\mathbf{Y}_v)_{v \in V}$;
 $w \sim v \iff w$ and v are neighbors

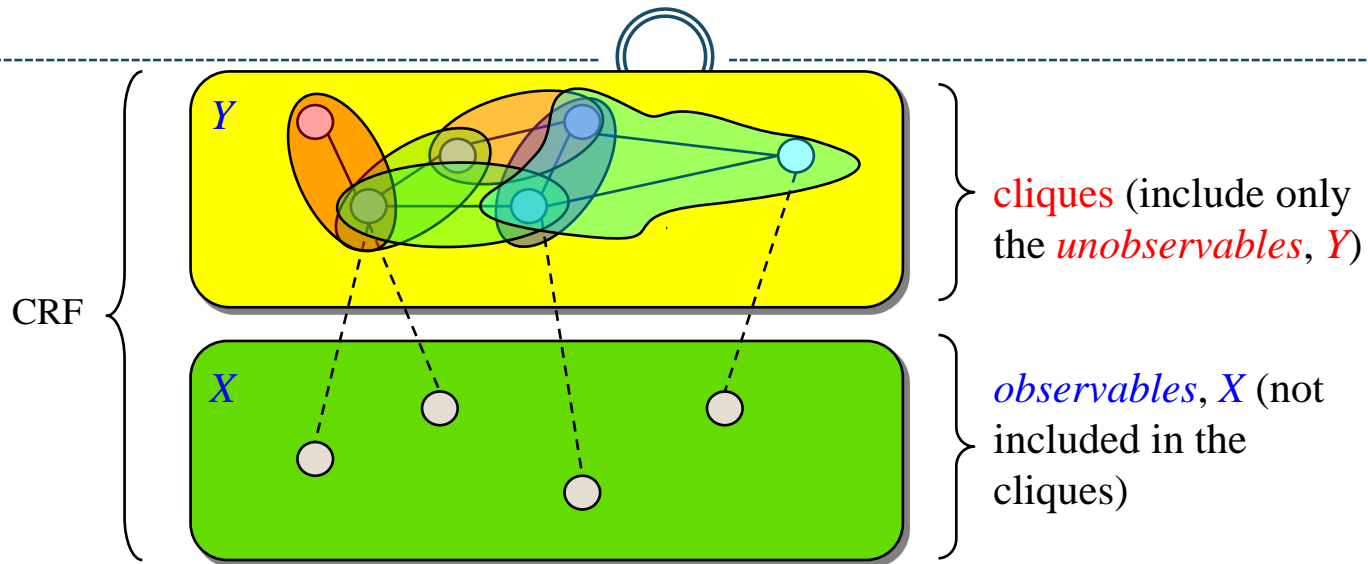
(\mathbf{X}, \mathbf{Y}) is a CRF, if $p(\mathbf{Y}_v | \mathbf{X}, \mathbf{Y}_w, w \neq v) = p(\mathbf{Y}_v | \mathbf{X}, \mathbf{Y}_w, w \sim v)$.



Note that in a CRF *we do not explicitly model any direct relationships between the observables (i.e., among the X)* (Lafferty *et al.*, 2001).

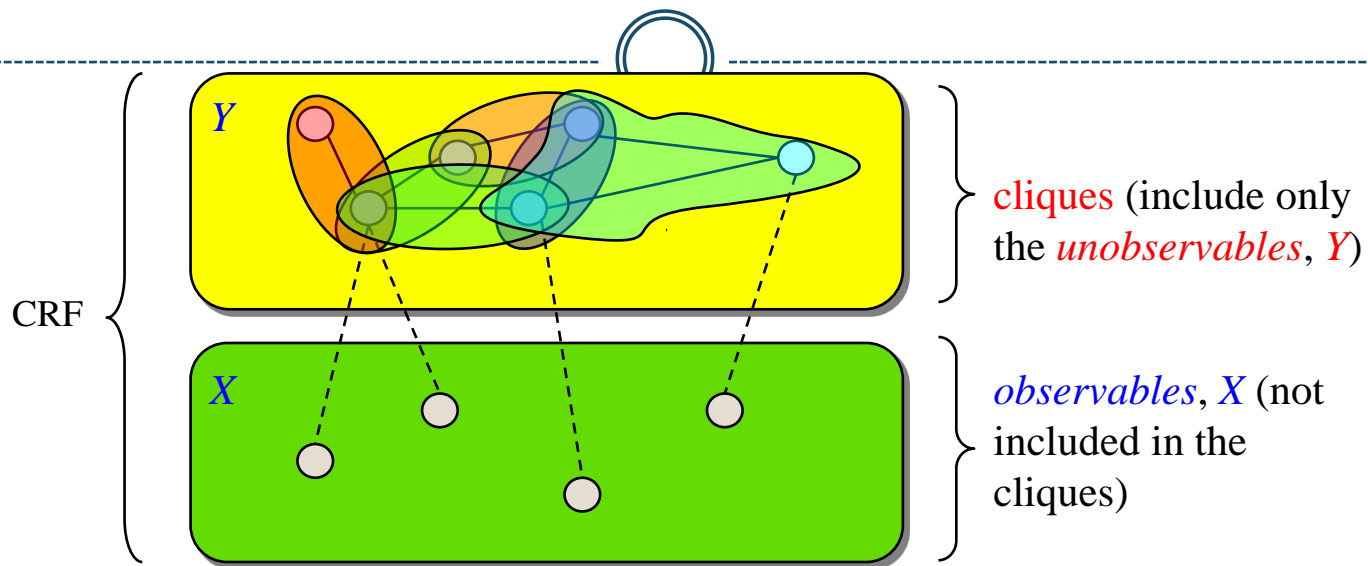
Hammersley-Clifford does not apply to X !

General CRF: visualization



- Divide \mathbf{y} MRF into cliques. The parameters inside each template are tied $\Phi_c(\mathbf{y}_c, \mathbf{x})$ --*potential functions*; functions for the template

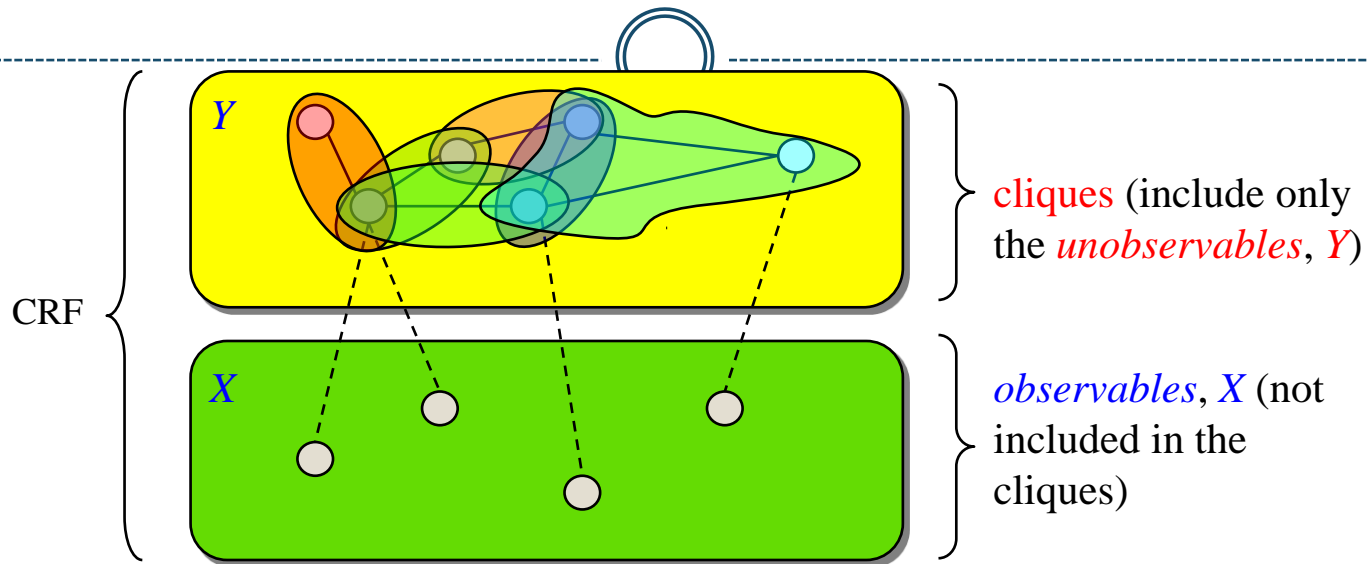
General CRF: visualization



- Divide \mathbf{y} MRF into cliques. The parameters inside each template are tied $\Phi_c(\mathbf{y}_c, \mathbf{x})$ --*potential functions*; functions for the template

$$p(\mathbf{y} | \mathbf{x}) = \frac{1}{Z(\mathbf{x})} e^{Q(\mathbf{y}, \mathbf{x})} = \frac{1}{\sum_{\mathbf{y}'} e^{Q(\mathbf{y}', \mathbf{x})}} e^{Q(\mathbf{y}, \mathbf{x})}, \quad Q(\mathbf{y}, \mathbf{x}) = \sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x})$$

General CRF: visualization

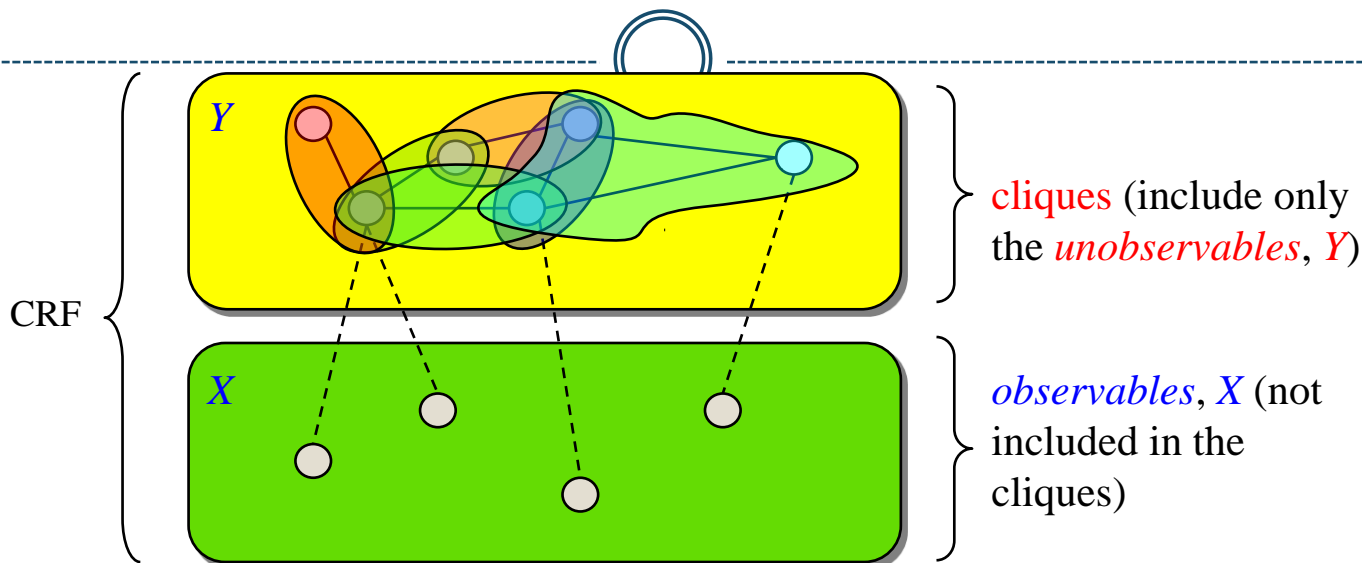


- Divide \mathbf{y} MRF into cliques. The parameters inside each template are tied $\Phi_c(\mathbf{y}_c, \mathbf{x})$ --*potential functions*; functions for the template

$$p(\mathbf{y} | \mathbf{x}) = \frac{1}{Z(\mathbf{x})} e^{Q(\mathbf{y}, \mathbf{x})} = \frac{1}{\sum_{\mathbf{y}'} e^{Q(\mathbf{y}', \mathbf{x})}} e^{Q(\mathbf{y}, \mathbf{x})}, \quad Q(\mathbf{y}, \mathbf{x}) = \sum_{c \in \mathcal{C}} \Phi_c(\mathbf{y}_c, \mathbf{x})$$

Note that we are not summing over \mathbf{x} in the denominator

General CRF: visualization



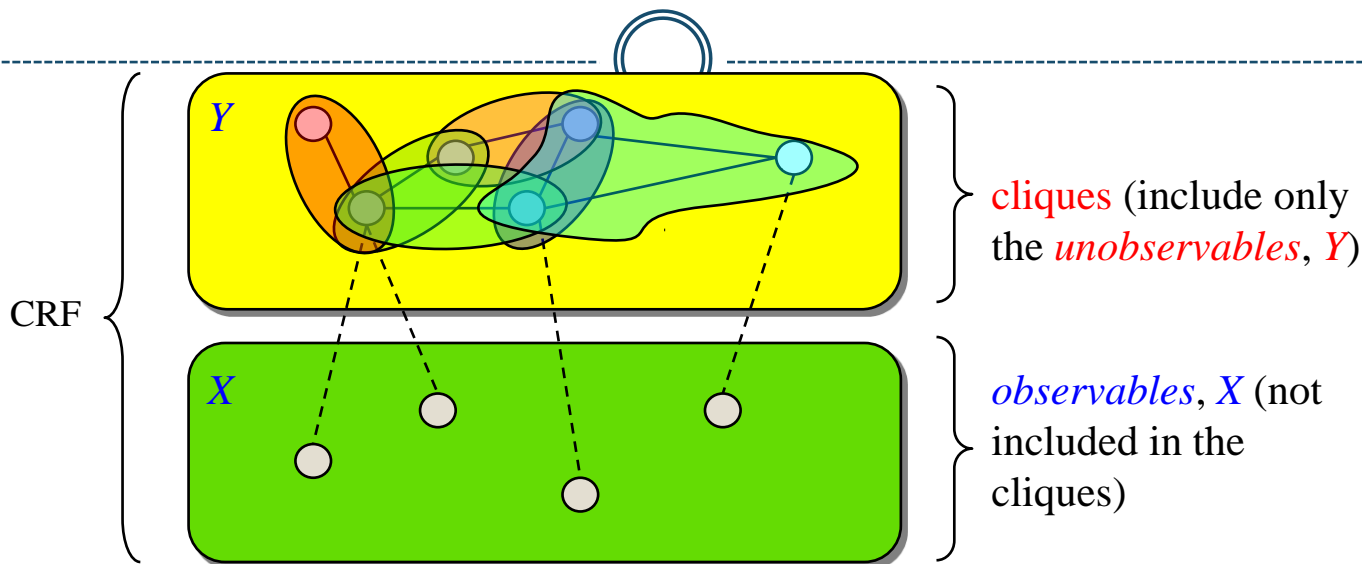
- Divide \mathbf{y} MRF into cliques. The parameters inside each template are tied $\Phi_c(\mathbf{y}_c, \mathbf{x})$ -- *potential functions*; functions for the template

$$p(\mathbf{y} | \mathbf{x}) = \frac{1}{Z(\mathbf{x})} e^{Q(\mathbf{y}, \mathbf{x})} = \frac{1}{\sum_{\mathbf{y}'} e^{Q(\mathbf{y}', \mathbf{x})}} e^{Q(\mathbf{y}, \mathbf{x})}, \quad Q(\mathbf{y}, \mathbf{x}) = \sum_{c \in \mathcal{C}} \Phi_c(\mathbf{y}_c, \mathbf{x})$$

Note that we are not summing over \mathbf{x} in the denominator

- The cliques contain only unobservables (\mathbf{y}); though, \mathbf{x} is an argument to Φ_c

General CRF: visualization



- Divide \mathbf{y} MRF into cliques. The parameters inside each template are tied $\Phi_c(\mathbf{y}_c, \mathbf{x})$ -- *potential functions*; functions for the template

$$p(\mathbf{y} | \mathbf{x}) = \frac{1}{Z(\mathbf{x})} e^{Q(\mathbf{y}, \mathbf{x})} = \frac{1}{\sum_{\mathbf{y}'} e^{Q(\mathbf{y}', \mathbf{x})}} e^{Q(\mathbf{y}, \mathbf{x})}, \quad Q(\mathbf{y}, \mathbf{x}) = \sum_{c \in \mathcal{C}} \Phi_c(\mathbf{y}_c, \mathbf{x})$$

Note that we are not summing over \mathbf{x} in the denominator

- The cliques contain only unobservables (\mathbf{y}); though, \mathbf{x} is an argument to Φ_c
- The probability $P_M(\mathbf{y} | \mathbf{x})$ is a *joint distribution* over the unobservables Y

General CRF: visualization



- A number of *ad hoc* modeling decisions are typically made with regard to the form of the potential functions.
- Φ_c is typically decomposed into a weighted sum of feature sensors f_i , producing:

$$p(\mathbf{y} \mid \mathbf{x}) = \frac{1}{Z} e^{Q(\mathbf{y}, \mathbf{x})}$$

$$Q(\mathbf{y}, \mathbf{x}) = \sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x})$$

General CRF: visualization



- A number of *ad hoc* modeling decisions are typically made with regard to the form of the potential functions.
- Φ_c is typically decomposed into a weighted sum of feature sensors f_i , producing:

$$\left. \begin{aligned} p(\mathbf{y} \mid \mathbf{x}) &= \frac{1}{Z} e^{Q(\mathbf{y}, \mathbf{x})} \\ Q(\mathbf{y}, \mathbf{x}) &= \sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x}) \\ \Phi_c(\mathbf{y}_c, \mathbf{x}) &= \sum_{i \in F} \lambda_i f_i(y_c, \mathbf{x}) \end{aligned} \right\}$$

General CRF: visualization



- A number of *ad hoc* modeling decisions are typically made with regard to the form of the potential functions.
- Φ_c is typically decomposed into a weighted sum of feature sensors f_i , producing:

$$\left. \begin{aligned} p(\mathbf{y} \mid \mathbf{x}) &= \frac{1}{Z} e^{Q(\mathbf{y}, \mathbf{x})} \\ Q(\mathbf{y}, \mathbf{x}) &= \sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x}) \\ \Phi_c(\mathbf{y}_c, \mathbf{x}) &= \sum_{i \in F} \lambda_i f_i(\mathbf{y}_c, \mathbf{x}) \end{aligned} \right\} P(\mathbf{y} \mid \mathbf{x}) = \frac{1}{Z} e^{\sum_{c \in C} \sum_{i \in F} \lambda_i f_i(\mathbf{y}_c, \mathbf{x})}$$

General CRF: visualization



- A number of *ad hoc* modeling decisions are typically made with regard to the form of the potential functions.
- Φ_c is typically decomposed into a weighted sum of feature sensors f_i , producing:

$$\left. \begin{aligned} p(\mathbf{y} \mid \mathbf{x}) &= \frac{1}{Z} e^{Q(\mathbf{y}, \mathbf{x})} \\ Q(\mathbf{y}, \mathbf{x}) &= \sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x}) \\ \Phi_c(\mathbf{y}_c, \mathbf{x}) &= \sum_{i \in F} \lambda_i f_i(\mathbf{y}_c, \mathbf{x}) \end{aligned} \right\} P(\mathbf{y} \mid \mathbf{x}) = \frac{1}{Z} e^{\sum_{c \in C} \sum_{i \in F} \lambda_i f_i(\mathbf{y}_c, \mathbf{x})}$$

- Back to the chain-CRF!

Cliques can be identified as *pairs* of adjacent Ys:

General CRF: visualization

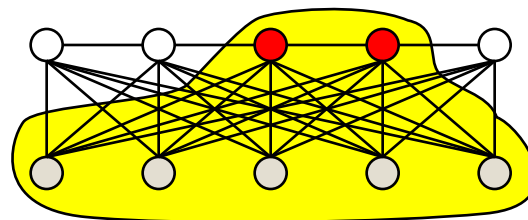


- A number of *ad hoc* modeling decisions are typically made with regard to the form of the potential functions.
- Φ_c is typically decomposed into a weighted sum of feature sensors f_i , producing:

$$\left. \begin{aligned}
 p(\mathbf{y} \mid \mathbf{x}) &= \frac{1}{Z} e^{Q(\mathbf{y}, \mathbf{x})} \\
 Q(\mathbf{y}, \mathbf{x}) &= \sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x}) \\
 \Phi_c(\mathbf{y}_c, \mathbf{x}) &= \sum_{i \in F} \lambda_i f_i(\mathbf{y}_c, \mathbf{x})
 \end{aligned} \right\} P(\mathbf{y} \mid \mathbf{x}) = \frac{1}{Z} e^{\sum_{c \in C} \sum_{i \in F} \lambda_i f_i(\mathbf{y}_c, \mathbf{x})}$$

- Back to the chain-CRF!

Cliques can be identified as *pairs* of adjacent Ys:



$$p(\mathbf{y} \mid \mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp \left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x}) \right)$$

$$F_j(\mathbf{y}, \mathbf{x}) = \sum_{i=1}^n f_j(y_{i-1}, y_i, \mathbf{x}, i),$$

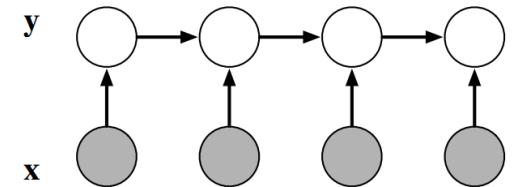
Chain CRFs vs. MEMM

- Linear-chain CRFs were originally introduced as an improvement to MEMM
- Maximum Entropy Markov Models (MEMM)
 - Transition probabilities are given by logistic regression

$$p_{\text{MEMM}}(\mathbf{y}|\mathbf{x}) = \prod_{t=1}^T p(y_t|y_{t-1}, \mathbf{x})$$

$$p(y_t|y_{t-1}, \mathbf{x}) = \frac{1}{Z_t(y_{t-1}, \mathbf{x})} \exp \left\{ \sum_{k=1}^K \theta_k f_k(y_t, y_{t-1}, \mathbf{x}_t) \right\}$$

$$Z_t(y_{t-1}, \mathbf{x}) = \sum_{y'} \exp \left\{ \sum_{k=1}^K \theta_k f_k(y', y_{t-1}, \mathbf{x}_t) \right\}$$

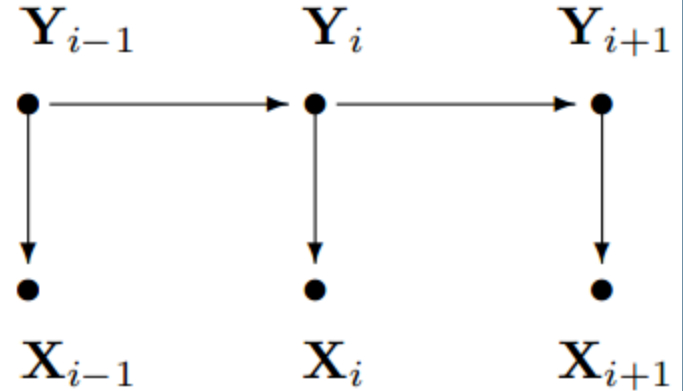


- Notice the per-state normalization
- Only dependent on the previous inputs; no dependence on the future states.
 - Label-bias problem

CRFs vs. MEMM vs. HMM



- HMM



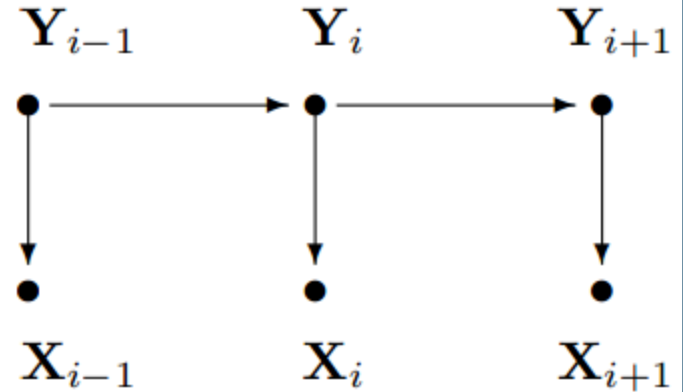
- MEMM

- CRF

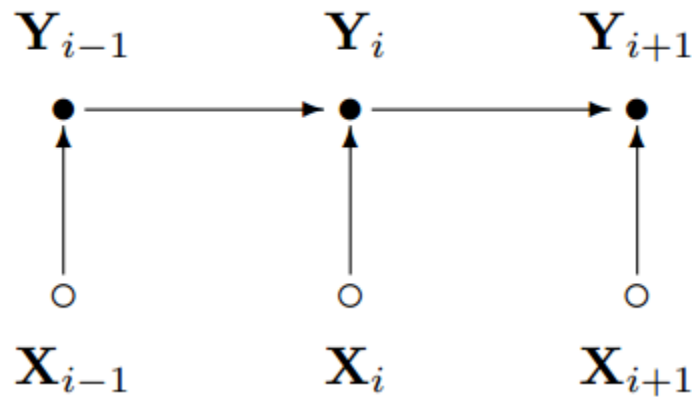
CRFs vs. MEMM vs. HMM



- HMM



- MEMM

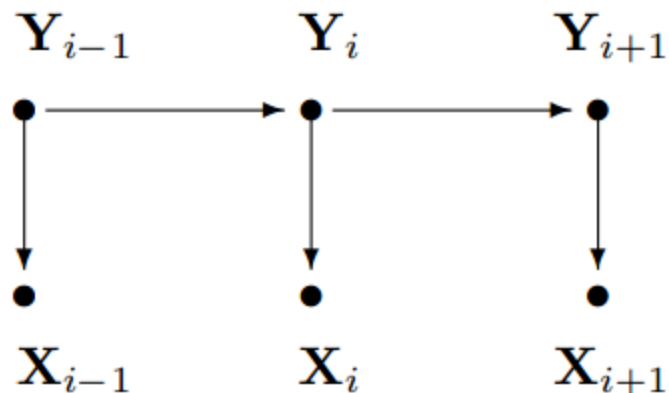


- CRF

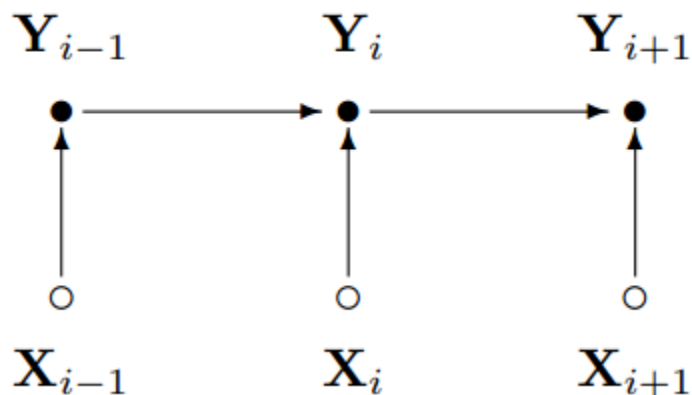
CRFs vs. MEMM vs. HMM



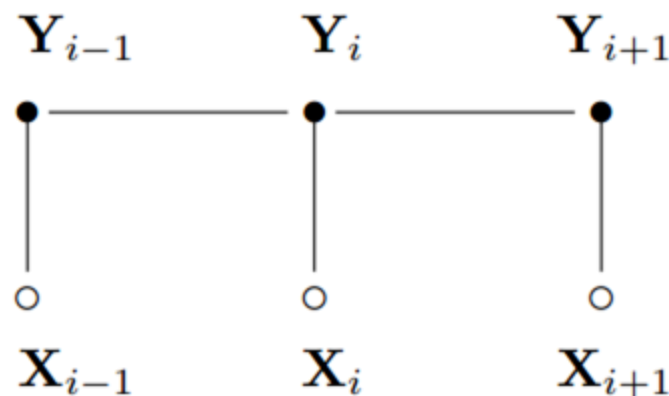
- HMM



- MEMM



- CRF



Outline



- Modeling
- **Inference**
 - General CRF
 - Chain CRF
- Training
- Applications

Inference



Inference



- Given the observations, $\{\mathbf{x}_i\}$ and parameters, we target to find the best state sequence
$$\mathbf{y}^* = \arg \max_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}).$$

Inference



- Given the observations, $\{\mathbf{x}_i\}$ and parameters, we target to find the best state sequence

$$\mathbf{y}^* = \arg \max_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}).$$

- For the general CRF:

$$\mathbf{y}^* = \arg \max_{\mathbf{y}} P(\mathbf{y} | \mathbf{x}) = \arg \max_{\mathbf{y}} \frac{1}{Z} e^{\sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x})} = \arg \max_{\mathbf{y}} \sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x})$$

Inference



- Given the observations, $\{\mathbf{x}_i\}$ and parameters, we target to find the best state sequence

$$\mathbf{y}^* = \arg \max_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}).$$

- For the general CRF:

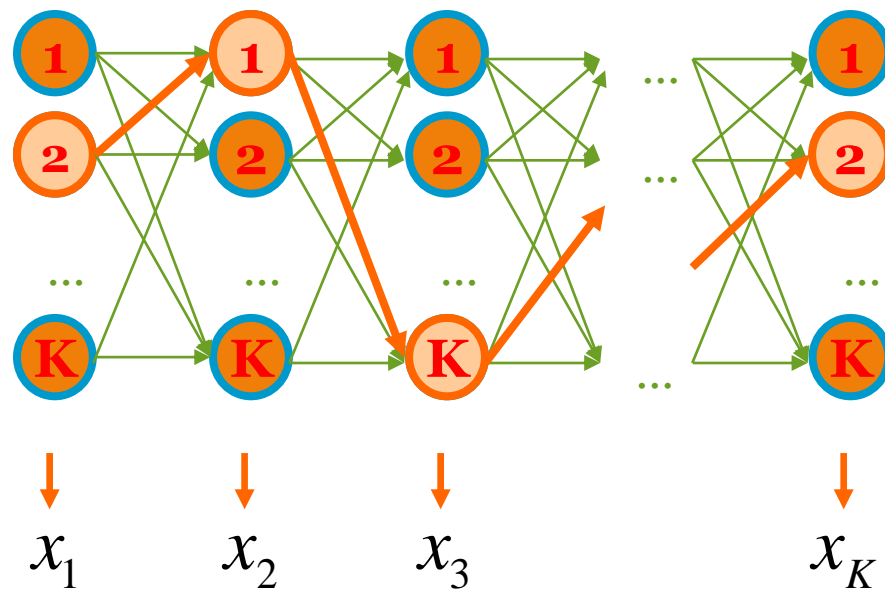
$$\mathbf{y}^* = \arg \max_{\mathbf{y}} P(\mathbf{y} | \mathbf{x}) = \arg \max_{\mathbf{y}} \frac{1}{Z} e^{\sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x})} = \arg \max_{\mathbf{y}} \sum_{c \in C} \Phi_c(\mathbf{y}_c, \mathbf{x})$$

- For general graphs, the problem of exact inference in CRFs is intractable
 - Approximate methods ! A large literature ...

Inference in HMM



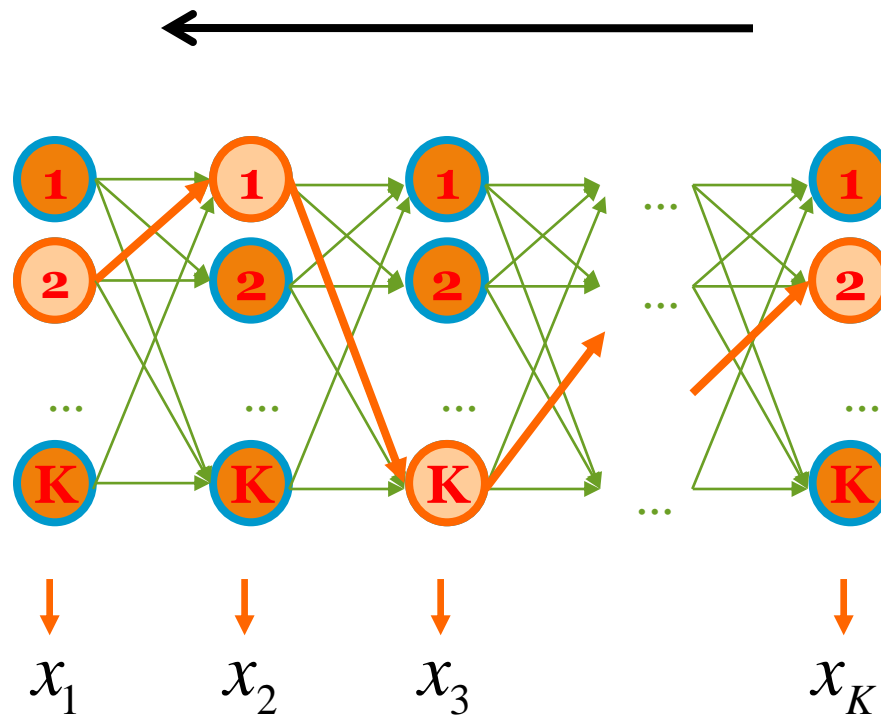
- Dynamic Programming:



Inference in HMM



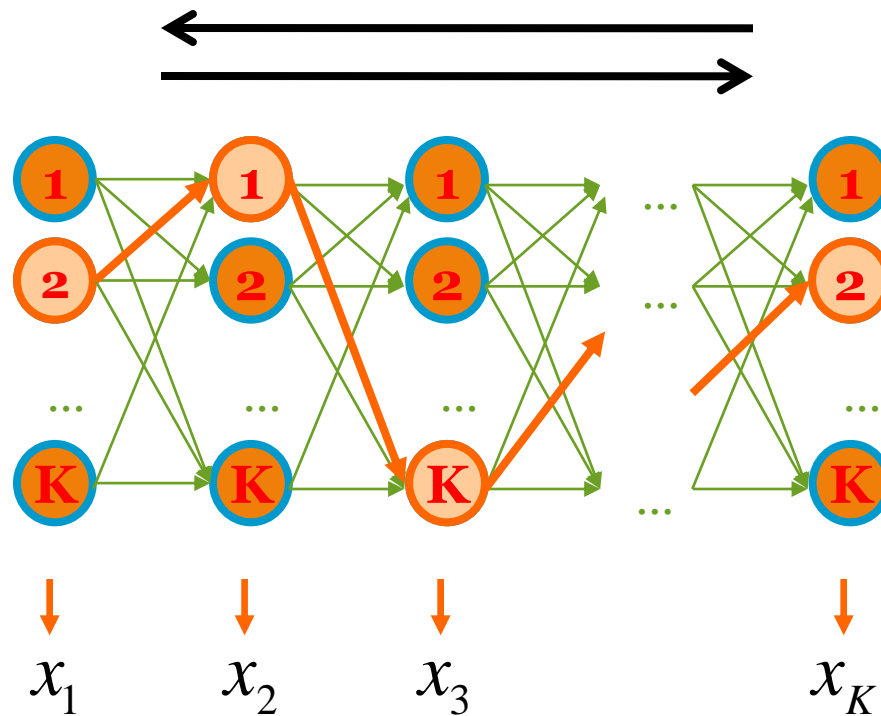
- Dynamic Programming:
 - Forward



Inference in HMM



- Dynamic Programming:
 - Forward
 - Backward



Parameter Learning: Chain CRF



- Chain CRF could be done using dynamic programming

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp\left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x})\right) \quad F_j(\mathbf{y}, \mathbf{x}) = \sum_{i=1}^n f_j(y_{i-1}, y_i, \mathbf{x}, i),$$

Parameter Learning: Chain CRF



- Chain CRF could be done using dynamic programming

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp\left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x})\right) \quad F_j(\mathbf{y}, \mathbf{x}) = \sum_{i=1}^n f_j(y_{i-1}, y_i, \mathbf{x}, i),$$

- Assume $\mathcal{Y} \in \mathcal{Y}$
- Naively doing could be intractable: $n^{|\mathcal{Y}|}$

Parameter Learning: Chain CRF



- Chain CRF could be done using dynamic programming

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp\left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x})\right) \quad F_j(\mathbf{y}, \mathbf{x}) = \sum_{i=1}^n f_j(y_{i-1}, y_i, \mathbf{x}, i),$$

- Assume $y \in \mathcal{Y}$
- Naively doing could be intractable: $n^{|\mathcal{Y}|}$
- Define a matrix $\{M_i(\mathbf{x}) | i = 1, \dots, n + 1\}$ with size $|\mathcal{Y}| \times |\mathcal{Y}|$

$$M_i(y', y|\mathbf{x}) = \exp\left(\sum_j \lambda_j f_j(y', y, \mathbf{x}, i)\right)$$

Parameter Learning: Chain CRF



- Chain CRF could be done using dynamic programming

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \exp\left(\sum_j \lambda_j F_j(\mathbf{y}, \mathbf{x})\right) \quad F_j(\mathbf{y}, \mathbf{x}) = \sum_{i=1}^n f_j(y_{i-1}, y_i, \mathbf{x}, i),$$

- Assume $\mathcal{Y} \in \mathcal{Y}$
- Naively doing could be intractable: $n^{|\mathcal{Y}|}$
- Define a matrix $\{M_i(\mathbf{x}) | i = 1, \dots, n+1\}$ with size $|\mathcal{Y} \times \mathcal{Y}|$

$$M_i(y', y|\mathbf{x}) = \exp\left(\sum_j \lambda_j f_j(y', y, \mathbf{x}, i)\right)$$

$$p(\mathbf{y}|\mathbf{x}, \boldsymbol{\lambda}) = \frac{1}{Z(\mathbf{x})} \prod_{i=1}^{n+1} M_i(y_{i-1}, y_i|\mathbf{x})$$

$$Z(\mathbf{x}) = \left[\prod_{i=1}^{n+1} M_i(\mathbf{x}) \right]_{\text{start, end}}$$

Parameter Learning: Chain CRF



- By defining the following forward and backward parameters,

Parameter Learning: Chain CRF



- By defining the following forward and backward parameters,

$$\alpha_i(\mathbf{x})^T = \alpha_{i-1}(\mathbf{x})^T M_i(\mathbf{x})$$

$$\alpha_0(y|\mathbf{x}) = \begin{cases} 1 & \text{if } y = \text{start} \\ 0 & \text{otherwise} \end{cases}$$

Parameter Learning: Chain CRF



- By defining the following forward and backward parameters,

$$\beta_i(\mathbf{x}) = M_{i+1}(\mathbf{x})\beta_{i+1}(\mathbf{x}) \quad \alpha_i(\mathbf{x})^T = \alpha_{i-1}(\mathbf{x})^T M_i(\mathbf{x})$$

$$\beta_{n+1}(y|\mathbf{x}) = \begin{cases} 1 & \text{if } y = \text{stop} \\ 0 & \text{otherwise} \end{cases} \quad \alpha_0(y|\mathbf{x}) = \begin{cases} 1 & \text{if } y = \text{start} \\ 0 & \text{otherwise} \end{cases}$$

Parameter Learning: Chain CRF



- By defining the following forward and backward parameters,

$$\beta_i(\mathbf{x}) = M_{i+1}(\mathbf{x})\beta_{i+1}(\mathbf{x}) \quad \alpha_i(\mathbf{x})^T = \alpha_{i-1}(\mathbf{x})^T M_i(\mathbf{x})$$

$$\beta_{n+1}(y|\mathbf{x}) = \begin{cases} 1 & \text{if } y = \text{stop} \\ 0 & \text{otherwise} \end{cases} \quad \alpha_0(y|\mathbf{x}) = \begin{cases} 1 & \text{if } y = \text{start} \\ 0 & \text{otherwise} \end{cases}$$

$$Z(\mathbf{x}) = \sum_{i \in S} \alpha_T(i).$$

$$Z(\mathbf{x}) = \beta_0(y_0)$$

Inference: Chain-CRF



- The inference of linear-chain CRF is very similar to that of HMM
- We can write the marginal distribution:

$$p(Y_{i-1} = y', Y_i = y | \mathbf{x}^{(k)}, \boldsymbol{\lambda}) = \frac{\alpha_{i-1}(y' | \mathbf{x}) M_i(y', y | \mathbf{x}) \beta_i(y | \mathbf{x})}{Z(\mathbf{x})}$$

- Solve **Chain-CRF** using **Dynamic Programming** (Similar to Viterbi)!

Inference: Chain-CRF



- The inference of linear-chain CRF is very similar to that of HMM
- We can write the marginal distribution:

$$p(Y_{i-1} = y', Y_i = y | \mathbf{x}^{(k)}, \boldsymbol{\lambda}) = \frac{\alpha_{i-1}(y' | \mathbf{x}) M_i(y', y | \mathbf{x}) \beta_i(y | \mathbf{x})}{Z(\mathbf{x})}$$

- Solve **Chain-CRF** using **Dynamic Programming** (Similar to Viterbi)!
- 1. First computing α for all t (forward), then compute β for all t (backward).
- 2. Return the marginal distributions computed.
- 3. Run viterbi to find the optimal sequence $n. | \mathcal{Y} |^2$

Outline



- Modeling
- Inference
- **Training**
 - General CRF
 - Some notes on approximate learning
- Applications

Parameter Learning



- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.

Parameter Learning



- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.
- For chain or tree structured CRFs, they can be trained by maximum likelihood

Parameter Learning



- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.
- For chain or tree structured CRFs, they can be trained by maximum likelihood
 - The objective function for chain-CRF is convex(see Lafferty et al(2001)).

Parameter Learning



- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.
- For chain or tree structured CRFs, they can be trained by maximum likelihood
 - The objective function for chain-CRF is convex(see Lafferty et al(2001)).
- General CRFs are intractable hence approximation solutions are necessary

Parameter Learning

-
- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the mode.

Parameter Learning



- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.
- Conditional log-likelihood for a general CRF:

Parameter Learning

- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.
- Conditional log-likelihood for a general CRF:

$$\mathcal{L}(\boldsymbol{\lambda}) = \sum_k \left[\log \frac{1}{Z(\mathbf{x}^{(k)})} + \sum_j \lambda_j F_j(\mathbf{y}^{(k)}, \mathbf{x}^{(k)}) \right]$$

$$\frac{\partial \mathcal{L}(\boldsymbol{\lambda})}{\partial \lambda_j} = E_{\tilde{p}(\mathbf{Y}, \mathbf{X})} [F_j(\mathbf{Y}, \mathbf{X})] - \sum_k E_{p(\mathbf{Y} | \mathbf{x}^{(k)}, \boldsymbol{\lambda})} [F_j(\mathbf{Y}, \mathbf{x}^{(k)})]$$

Empirical
Distribution

Parameter Learning

- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.
- Conditional log-likelihood for a general CRF:

$$\mathcal{L}(\boldsymbol{\lambda}) = \sum_k \left[\log \frac{1}{Z(\mathbf{x}^{(k)})} + \sum_j \lambda_j F_j(\mathbf{y}^{(k)}, \mathbf{x}^{(k)}) \right]$$

$$\frac{\partial \mathcal{L}(\boldsymbol{\lambda})}{\partial \lambda_j} = E_{\tilde{p}(\mathbf{Y}, \mathbf{X})} [F_j(\mathbf{Y}, \mathbf{X})] - \sum_k E_{p(\mathbf{Y} | \mathbf{x}^{(k)}, \boldsymbol{\lambda})} [F_j(\mathbf{Y}, \mathbf{x}^{(k)})]$$

Empirical
Distribution

Parameter Learning

- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.
- Conditional log-likelihood for a general CRF:

$$\mathcal{L}(\boldsymbol{\lambda}) = \sum_k \left[\log \frac{1}{Z(\mathbf{x}^{(k)})} + \sum_j \lambda_j F_j(\mathbf{y}^{(k)}, \mathbf{x}^{(k)}) \right]$$

$$\frac{\partial \mathcal{L}(\boldsymbol{\lambda})}{\partial \lambda_j} = E_{\tilde{p}(\mathbf{Y}, \mathbf{X})} [F_j(\mathbf{Y}, \mathbf{X})] - \sum_k E_{p(\mathbf{Y} | \mathbf{x}^{(k)}, \boldsymbol{\lambda})} [F_j(\mathbf{Y}, \mathbf{x}^{(k)})]$$

Empirical
Distribution

Hard to calculate!

Parameter Learning

- Given the training data, $\{\mathbf{x}^{(i)}, \mathbf{y}^{(i)}\}_{i=1}^N$, we wish to learn parameters of the model.
- Conditional log-likelihood for a general CRF:

$$\mathcal{L}(\boldsymbol{\lambda}) = \sum_k \left[\log \frac{1}{Z(\mathbf{x}^{(k)})} + \sum_j \lambda_j F_j(\mathbf{y}^{(k)}, \mathbf{x}^{(k)}) \right]$$

$$\frac{\partial \mathcal{L}(\boldsymbol{\lambda})}{\partial \lambda_j} = E_{\tilde{p}(\mathbf{Y}, \mathbf{X})} [F_j(\mathbf{Y}, \mathbf{X})] - \sum_k E_{p(\mathbf{Y} | \mathbf{x}^{(k)}, \boldsymbol{\lambda})} [F_j(\mathbf{Y}, \mathbf{x}^{(k)})]$$

Empirical
Distribution

Hard to calculate!

- It is not possible to analytically determine the parameter values that maximize the log-likelihood – setting the gradient to zero and solving for $\boldsymbol{\lambda}$ does not always yield a closed form solution. (Almost always)

Parameter Learning



Parameter Learning



- This could be done using gradient descent

$$\lambda \propto \max_{\lambda} \mathcal{L}(\lambda; y | x) \propto \max_{\lambda} \log \sum_{i=1}^N p(\mathbf{y} | \mathbf{x}; \lambda)$$

Parameter Learning



- This could be done using gradient descent

$$\lambda \propto \max_{\lambda} \mathcal{L}(\lambda; y | x) \propto \max_{\lambda} \log \sum_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}; \lambda)$$

$$\lambda_{i+1} \leftarrow \lambda_i + \alpha \cdot \nabla_{\lambda} \mathcal{L}(\lambda; y | \bar{\mathbf{x}}^{i=1})$$

Parameter Learning



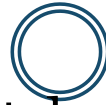
- This could be done using gradient descent

$$\lambda \propto \max_{\lambda} \mathcal{L}(\lambda; y | x) \propto \max_{\lambda} \log \sum_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}; \lambda)$$

$$\lambda_{i+1} \leftarrow \lambda_i + \alpha \cdot \nabla_{\lambda} \mathcal{L}(\lambda; y | \bar{\mathbf{x}}^{i-1})$$

- Until we reach convergence

Parameter Learning



- This could be done using gradient descent

$$\lambda \propto \max_{\lambda} \mathcal{L}(\lambda; y | x) \propto \max_{\lambda} \log \sum_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}; \lambda)$$

$$\lambda_{i+1} \leftarrow \lambda_i + \alpha \cdot \nabla_{\lambda} \mathcal{L}(\lambda; y | \bar{\mathbf{x}}^{i-1})$$

- Until we reach convergence

$$|\mathcal{L}(\lambda_{i+1}; y | x) - \mathcal{L}(\lambda_i; y | x)| < \epsilon$$

Parameter Learning



- This could be done using gradient descent

$$\lambda \propto \max_{\lambda} \mathcal{L}(\lambda; y | x) \propto \max_{\lambda} \log \sum_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}; \lambda)$$

$$\lambda_{i+1} \leftarrow \lambda_i + \alpha \cdot \nabla_{\lambda} \mathcal{L}(\lambda; y | \bar{\mathbf{x}}^{i-1})$$

- Until we reach convergence

$$|\mathcal{L}(\lambda_{i+1}; y | x) - \mathcal{L}(\lambda_i; y | x)| < \epsilon$$

- Or any other optimization:

- Quasi-Newton methods: BFGS [Bertsekas, 1999] or L-BFGS [Byrd, 1994]

Parameter Learning



- This could be done using gradient descent

$$\lambda \propto \max_{\lambda} \mathcal{L}(\lambda; y | x) \propto \max_{\lambda} \log \sum_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}; \lambda)$$

$$\lambda_{i+1} \leftarrow \lambda_i + \alpha \cdot \nabla_{\lambda} \mathcal{L}(\lambda; y | \bar{\mathbf{x}}^i)$$

- Until we reach convergence

$$|\mathcal{L}(\lambda_{i+1}; y | x) - \mathcal{L}(\lambda_i; y | x)| < \epsilon$$

- Or any other optimization:

- Quasi-Newton methods: BFGS [Bertsekas, 1999] or L-BFGS [Byrd, 1994]

- General CRFs are intractable hence approximation solutions are necessary

Parameter Learning



- This could be done using gradient descent

$$\lambda \propto \max_{\lambda} \mathcal{L}(\lambda; y | x) \propto \max_{\lambda} \log \sum_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}; \lambda)$$

$$\lambda_{i+1} \leftarrow \lambda_i + \alpha \cdot \nabla_{\lambda} \mathcal{L}(\lambda; y | \bar{\mathbf{x}})$$

- Until we reach convergence

$$|\mathcal{L}(\lambda_{i+1}; y | x) - \mathcal{L}(\lambda_i; y | x)| < \epsilon$$

- Or any other optimization:

- Quasi-Newton methods: BFGS [Bertsekas, 1999] or L-BFGS [Byrd, 1994]

- General CRFs are intractable hence approximation solutions are necessary

Compared with Markov chains, CRF's should be more discriminative, much slower to train and possibly more susceptible to over-training.

Parameter Learning



- This could be done using gradient descent

$$\lambda \propto \max_{\lambda} \mathcal{L}(\lambda; y | x) \propto \max_{\lambda} \log \sum_{\mathbf{y}} p(\mathbf{y} | \mathbf{x}; \lambda)$$

$$\lambda_{i+1} \leftarrow \lambda_i + \alpha \cdot \nabla_{\lambda} \mathcal{L}(\lambda; y | \bar{\mathbf{x}})$$

- Until we reach convergence

$$|\mathcal{L}(\lambda_{i+1}; y | x) - \mathcal{L}(\lambda_i; y | x)| < \epsilon$$

- Or any other optimization:

- Quasi-Newton methods: BFGS [Bertsekas, 1999] or L-BFGS [Byrd, 1994]

- General CRFs are intractable hence approximation solutions are necessary

Compared with Markov chains, CRF's should be more discriminative, much slower to train and possibly more susceptible to over-training.

- Regularization:

- σ is a regularization parameter

$$f_{\text{objective}}(\theta) = P_{\theta}(\mathbf{y} | \mathbf{x}) - \frac{\|\theta\|^2}{2\sigma^2}$$

Training (and Inference): General Case



- Approximate solution, to get faster inference.

Training (and Inference): General Case



- Approximate solution, to get faster inference.
- Treat inference as shortest path problem in the network consisting of paths(with costs)
 - Max Flow-Min Cut (Ford-Fulkerson, 1956)

Training (and Inference): General Case



- Approximate solution, to get faster inference.
- Treat inference as shortest path problem in the network consisting of paths(with costs)
 - Max Flow-Min Cut (Ford-Fulkerson, 1956)
- Pseudo-likelihood approximation:
 - Convert a CRF into separate patches; each consists of a hidden node and true values of neighbors; Run ML on separate patches
 - Efficient but may over-estimate inter-dependencies

Training (and Inference): General Case



- Approximate solution, to get faster inference.
- Treat inference as shortest path problem in the network consisting of paths(with costs)
 - Max Flow-Min Cut (Ford-Fulkerson, 1956)
- Pseudo-likelihood approximation:
 - Convert a CRF into separate patches; each consists of a hidden node and true values of neighbors; Run ML on separate patches
 - Efficient but may over-estimate inter-dependencies
- Belief propagation?!
 - variational inference algorithm
 - it is a direct generalization of the exact inference algorithms for linear-chain CRFs

Training (and Inference): General Case



- Approximate solution, to get faster inference.
- Treat inference as shortest path problem in the network consisting of paths(with costs)
 - Max Flow-Min Cut (Ford-Fulkerson, 1956)
- Pseudo-likelihood approximation:
 - Convert a CRF into separate patches; each consists of a hidden node and true values of neighbors; Run ML on separate patches
 - Efficient but may over-estimate inter-dependencies
- Belief propagation?!
 - variational inference algorithm
 - it is a direct generalization of the exact inference algorithms for linear-chain CRFs
- Sampling based method(MCMC)

Training (and Inference): General Case



- Approximate solution, to get faster inference.
- Treat inference as shortest path problem in the network consisting of paths(with costs)
 - Max Flow-Min Cut (Ford-Fulkerson, 1956)
- Pseudo-likelihood approximation:
 - Convert a CRF into separate patches; each consists of a hidden node and true values of neighbors; Run ML on separate patches
 - Efficient but may over-estimate inter-dependencies
- Belief propagation?!
 - variational inference algorithm
 - it is a direct generalization of the exact inference algorithms for linear-chain CRFs
- Sampling based method(MCMC)

sorry about
that, man!



CRF frontiers



- Bayesian CRF:
 - Because of the large number of parameters in typical applications of CRFs



CRF frontiers



- Bayesian CRF:
 - Because of the large number of parameters in typical applications of CRFs
 - prone to overfitting.



CRF frontiers



- Bayesian CRF:
 - Because of the large number of parameters in typical applications of CRFs
 - prone to overfitting.
 - Regularization?
 -

CRF frontiers



- Bayesian CRF:
 - Because of the large number of parameters in typical applications of CRFs
 - prone to overfitting.
 - Regularization?
 - Instead of $\mathbf{y}^* = \max_{\mathbf{y}} p(\mathbf{y}|\mathbf{x}; \hat{\theta})$.
 - $\mathbf{y}^* = \max_{\mathbf{y}} \int p(\mathbf{y}|\mathbf{x}; \theta) p(\theta | \mathbf{x}^{(1)}, \mathbf{y}^{(1)}, \dots, \mathbf{x}^{(N)}, \mathbf{y}^{(\bar{N})}) d\theta$.
 - Too complicated! How can we approximate this?

CRF frontiers



- Bayesian CRF:
 - Because of the large number of parameters in typical applications of CRFs
 - prone to overfitting.
 - Regularization?
 - Instead of $\mathbf{y}^* = \max_{\mathbf{y}} p(\mathbf{y}|\mathbf{x}; \hat{\theta})$.
 - $\mathbf{y}^* = \max_{\mathbf{y}} \int p(\mathbf{y}|\mathbf{x}; \theta) p(\theta|\mathbf{x}^{(1)}, \mathbf{y}^{(1)}, \dots, \mathbf{x}^{(N)}, \mathbf{y}^{(N)}) d\theta$.
 - Too complicated! How can we approximate this?
- Semi-supervised CRF:
 - The need to have big labeled data!
 - Unlike in generative models, it is less obvious how to incorporate unlabelled data into a conditional criterion, because the unlabelled data is a sample from the distribution $p(\mathbf{x})$

Outline

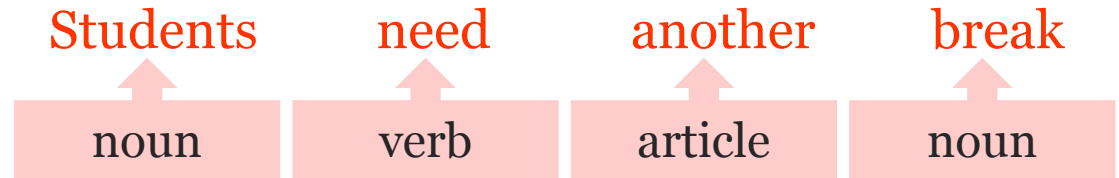


- Modeling
- Inference
- Training
- **Some Applications**

Some applications: Part-of-Speech-Tagging



- POS(part of speech) tagging; the identification of words as nouns, verbs, adjectives, adverbs, etc.



- CRF features:

Feature Type	Description
Transition	$\forall k, k' y_i = k \text{ and } y_{i+1} = k'$
Word	$\forall k, w y_i = k \text{ and } x_i = w$ $\forall k, w y_i = k \text{ and } x_{i-1} = w$ $\forall k, w y_i = k \text{ and } x_{i+1} = w$ $\forall k, w, w' y_i = k \text{ and } x_i = w \text{ and } x_{i-1} = w'$ $\forall k, w, w' y_i = k \text{ and } x_i = w \text{ and } x_{i+1} = w'$
Orthography: Suffix	$\forall s \text{ in } \{\text{"ing"}, \text{"ed"}, \text{"ogy"}, \text{"s"}, \text{"ly"}, \text{"ion"}, \text{"tion"}, \text{"ity"}, \dots\} \text{ and } \forall k y_i = k \text{ and } x_i \text{ ends with } s$
Orthography: Punctuation	$\forall k y_i = k \text{ and } x_i \text{ is capitalized}$ $\forall k y_i = k \text{ and } x_i \text{ is hyphenated}$...

Is HMM(Gen.) better or CRF(Disc.)

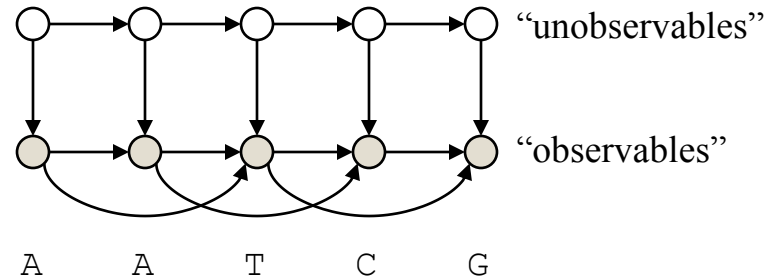


- If your application gives you good structural information such that could be easily modeled by dependent distributions, and could be learnt tractably, go the generative way!

Is HMM(Gen.) better or CRF(Disc.)



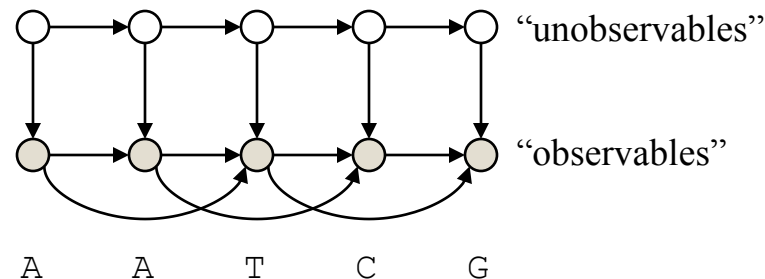
- If your application gives you good structural information such that could be easily modeled by dependent distributions, and could be learnt tractably, go the generative way!
- Ex. Higher-order emissions from individual states



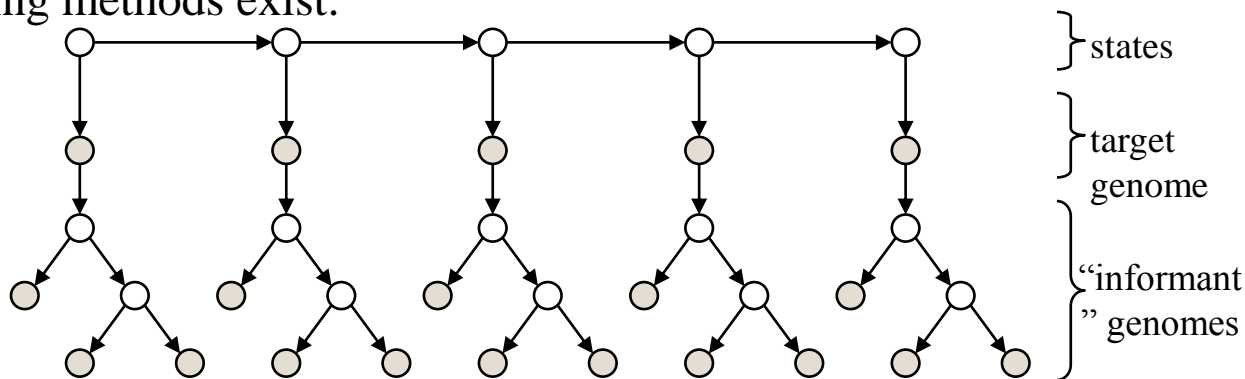
Is HMM(Gen.) better or CRF(Disc.)



- If your application gives you good structural information such that could be easily modeled by dependent distributions, and could be learnt tractably, go the generative way!
- Ex. Higher-order emissions from individual states



- Incorporating *evolutionary conservation* from an alignment: *PhyloHMM*, for which efficient decoding methods exist:



References



- J. Lafferty, A. McCallum, and F. Pereira. Conditional random fields: Probabilistic models for segmenting and labeling sequence data. In Proc. ICML01, 2001.
- Charles Elkan, “Log-linear Models and Conditional Random Field,” Notes for a tutorial at CIKM, 2008.
- Charles Sutton and Andrew McCallum, “An Introduction to Conditional Random Fields for Relational Learning,” MIT Press, 2006
- Slides: An Introduction to Conditional Random Field, Ching-Chun Hsiao
- Hanna M. Wallach , Conditional Random Fields: An Introduction, 2004
- Sutton, Charles, and Andrew McCallum. *An introduction to conditional random fields for relational learning*. Introduction to statistical relational learning. MIT Press, 2006.
- Sutton, Charles, and Andrew McCallum. "An introduction to conditional random fields." *arXiv preprint arXiv:1011.4088* (2010).
- B. Majoros, Conditional Random Fields, for eukaryotic gene prediction