CS5740: Natural Language Processing
Spring 2017

Recurrent Neural Networks

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Adapted from Yoav Goldberg's Book and slides by Sasha Rush

Overview

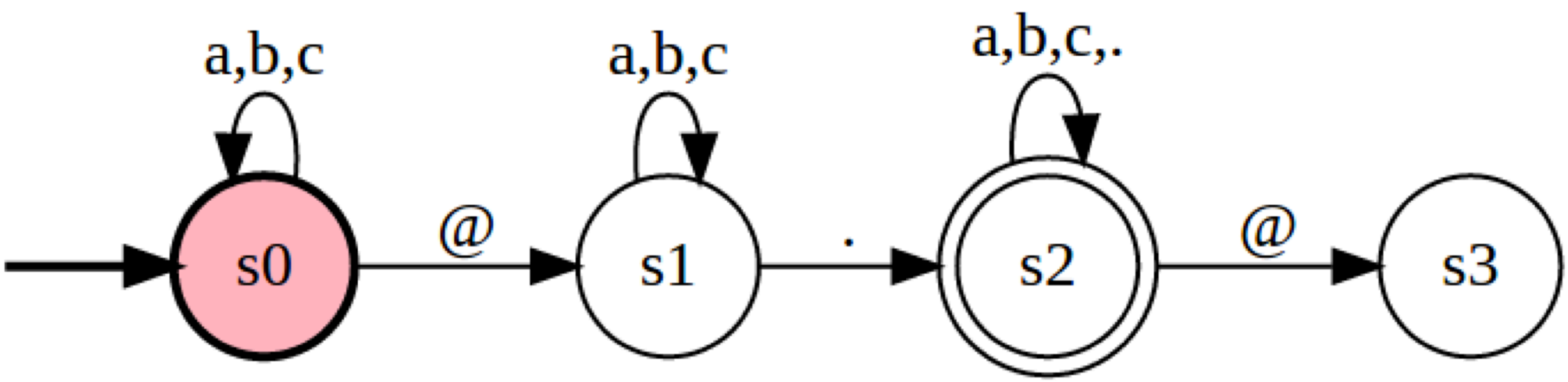
- Finite state models
- Recurrent neural networks (RNNs)
- Training RNNs
- RNN Models
- Long short-term memory (LSTM)

Text Classification

- Consider the example:
  - Goal: classify sentiment
    How can you not see this movie?
    You should not see this movie.
- Model: unigrams and bigrams
- How well will the classifier work?
  - Similar unigrams and bigrams
- Generally: need to maintain a **state** to capture distant influences

Finite State Machines

- Simple, classical way of representing state
- Current state: saves necessary past information
- Example: email address parsing



Deterministic Finite State Machines

- S – states
- Σ – vocabulary
- $s_0 \in S$ – start state
- $R: S \times \Sigma \to S$ – transition function

- What does it do?
  - Maps input $w_1, \ldots, w_n$ to states $s_1, \ldots, s_n$
  - For all $i \in \{1, \ldots, n\}$
$$s_i = R(s_{i-1}, w_i)$$
- Can we use it for POS tagging? Language modeling?

Types of State Machines

- Acceptor
  - Compute final state s_n and make a decision based on it: $y = O(s_n)$
- Transducers
  - Apply function $y_i = O(s_i)$ to produce output for each intermediate state
- Encoders
  - Compute final state s_n, and use it in another model

Recurrent Neural Networks

- Motivation:
  - Neural network model, but with state
  - How can we borrow ideas from FSMs?
- RNNs are FSMs …
  - … with a twist
  - No longer finite in the same sense

RNN

- $S = \ \mathbb{R}^{d_{hid}}$ - hidden state space
- $\Sigma = \mathbb{R}^{d_{in}}$ - input state space
- $\boldsymbol{s}_0 \in S$ - initial state vector
- $R : \mathbb{R}^{d_{in}} \times \mathbb{R}^{d_{hid}} \rightarrow \mathbb{R}^{d_{hid}}$ - transition function
- Simple definition of R:

$$R_{Elman}(\boldsymbol{s}, \boldsymbol{x}) = \tanh([\boldsymbol{x}, \boldsymbol{s}]\boldsymbol{W} + \boldsymbol{b})$$

* Notation: vectors and matrices are bold

Elman (1990)

RNN

- Map from dense sequence to dense representation
  - $\boldsymbol{x}_1, \dots, \boldsymbol{x}_n \to \boldsymbol{s}_1, \dots, \boldsymbol{s}_n$
  - For all $i \in \{1, \dots, n\}$
$$\boldsymbol{s}_i = R(\boldsymbol{s}_{i-1}, \boldsymbol{x})$$
  - R is parameterized, and parameters are shared between all steps
  - Example:

$$\boldsymbol{s}_4 = R(\boldsymbol{s}_3, \boldsymbol{x}_4) = \cdots = R(R(R(R(\boldsymbol{s}_0, \boldsymbol{x}_1), \boldsymbol{x}_2), \boldsymbol{x}_3), \boldsymbol{x}_4)$$

RNNs

- Hidden states $\boldsymbol{s}_i$ can be used in different ways
- Similar to finite state machines
  - Acceptor
  - Transducer
  - Encoder
- Output function maps vectors to symbols:

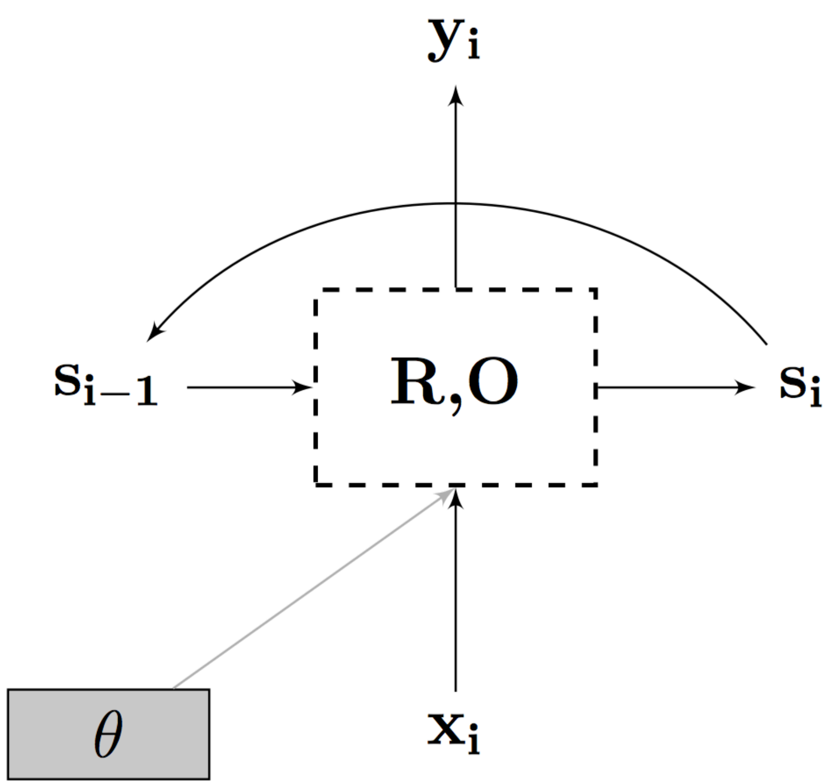
$$O: \mathbb{R}^{d_{hid}} \rightarrow \mathbb{R}^{d_{out}}$$

- For example: single layer + softmax

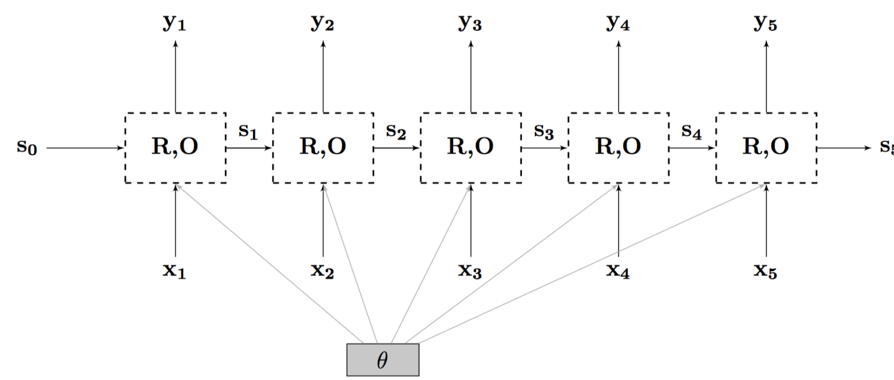
$$O(\boldsymbol{s}_i) = \mathrm{softmax}(\boldsymbol{s}_i \boldsymbol{W} + \boldsymbol{b})$$

Graphical Representation

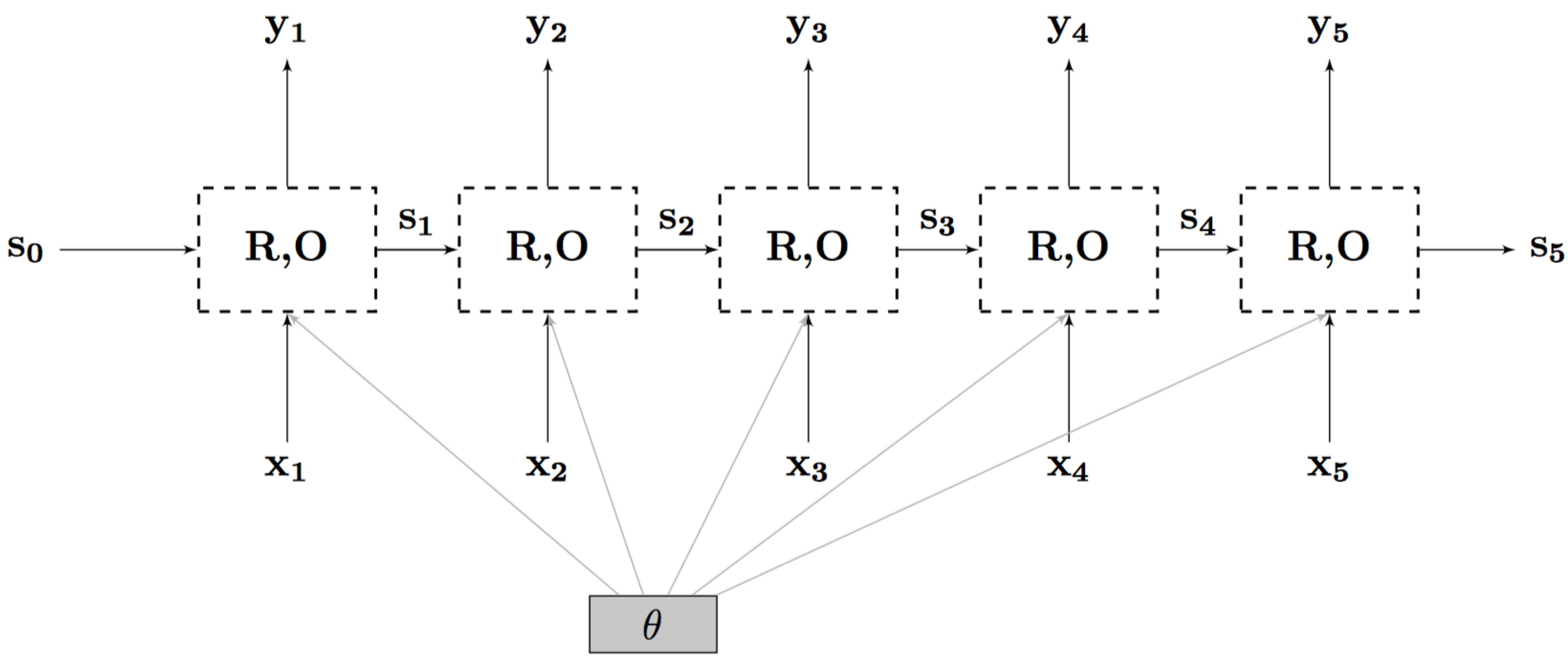
Recursive Representation



Unrolled Representation



Graphical Representation

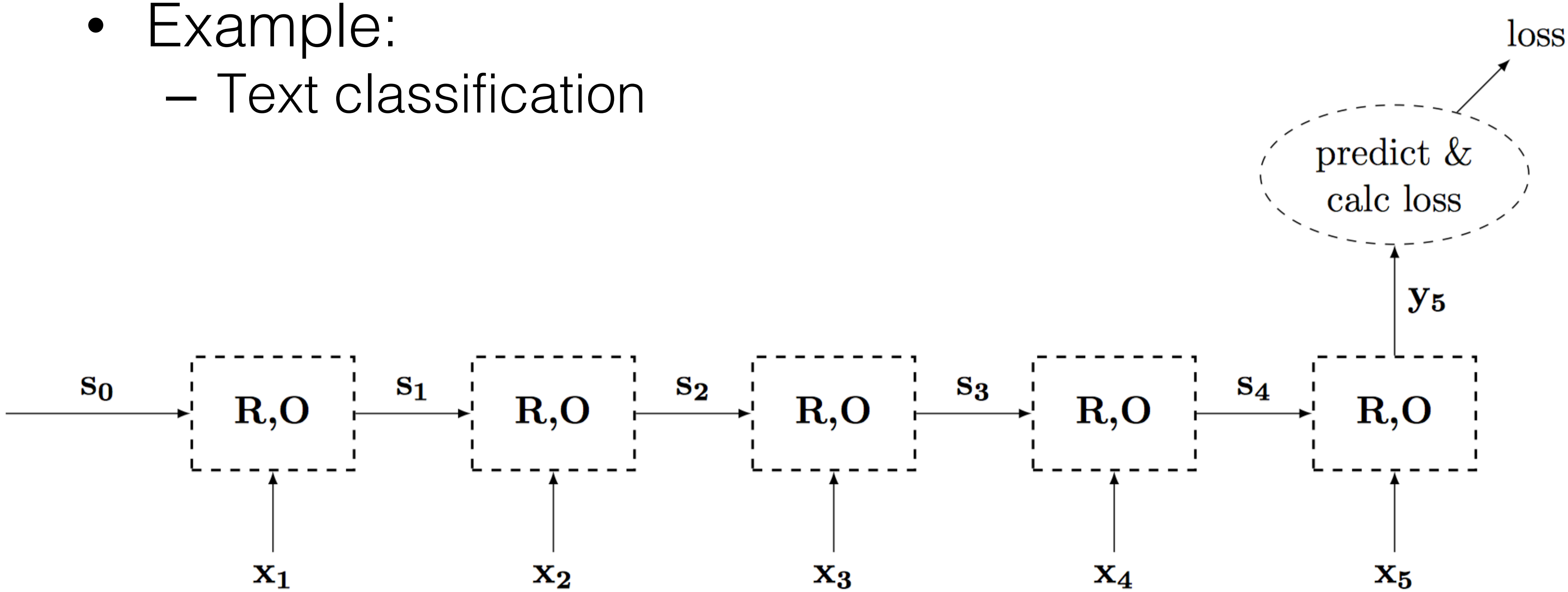


Training

- RNNs are trained with SGD and Backprop
- Define loss over outputs
  - Depends on supervision and task
- Backpropagation through time (BPTT)
  - Run forward propagation
  - Run backward propagation
  - Update all weights
- Weights are shared between time steps
  - Sum the contributions of each time step to the gradient
- Inefficient
  - Batch helps, common but tricky to implement with variable-size models

RNN: Acceptor Architecture

- Only care about the output from the last hidden state
- Train: supervised, loss on prediction
- Example:
  - Text classification



Language Modeling

- Input: $X = x_1, \ldots, x_n$
- Goal: compute $p(X)$
- Bi-gram decomposition:

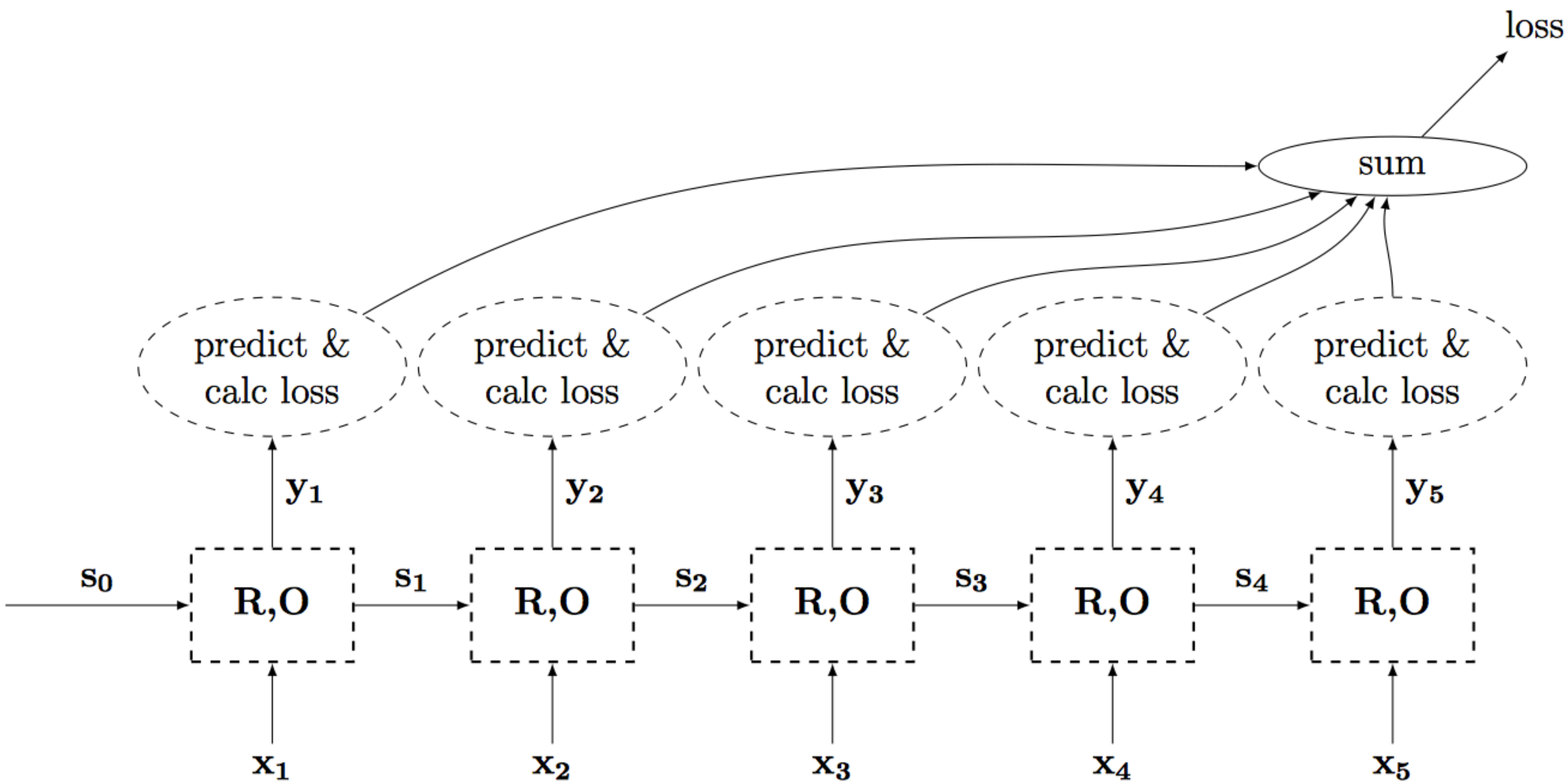
$$p(X) = \prod_{i=1}^{n} p(x_i \mid x_{i-1})$$

- With RNNs, can do non-Markovian models:

$$p(X) = \prod_{i=1}^{n} p(x_i \mid x_1, \ldots, x_{i-1})$$

RNN: Transducer Architecture

- Predict output for every time step



Language Modeling

- Input: $X = x_1, \ldots, x_n$
- Goal: compute $p(X)$
- Model:

$$p(X) = \prod_{i=1}^{n} p(x_i \mid x_1, \ldots, x_{i-1})$$

$$p(\, x_i \mid x_1, \ldots, x_{i-1}\,) = O(\boldsymbol{s}_i) = O(R(\boldsymbol{s}_{i-1}, \boldsymbol{x}_i))$$

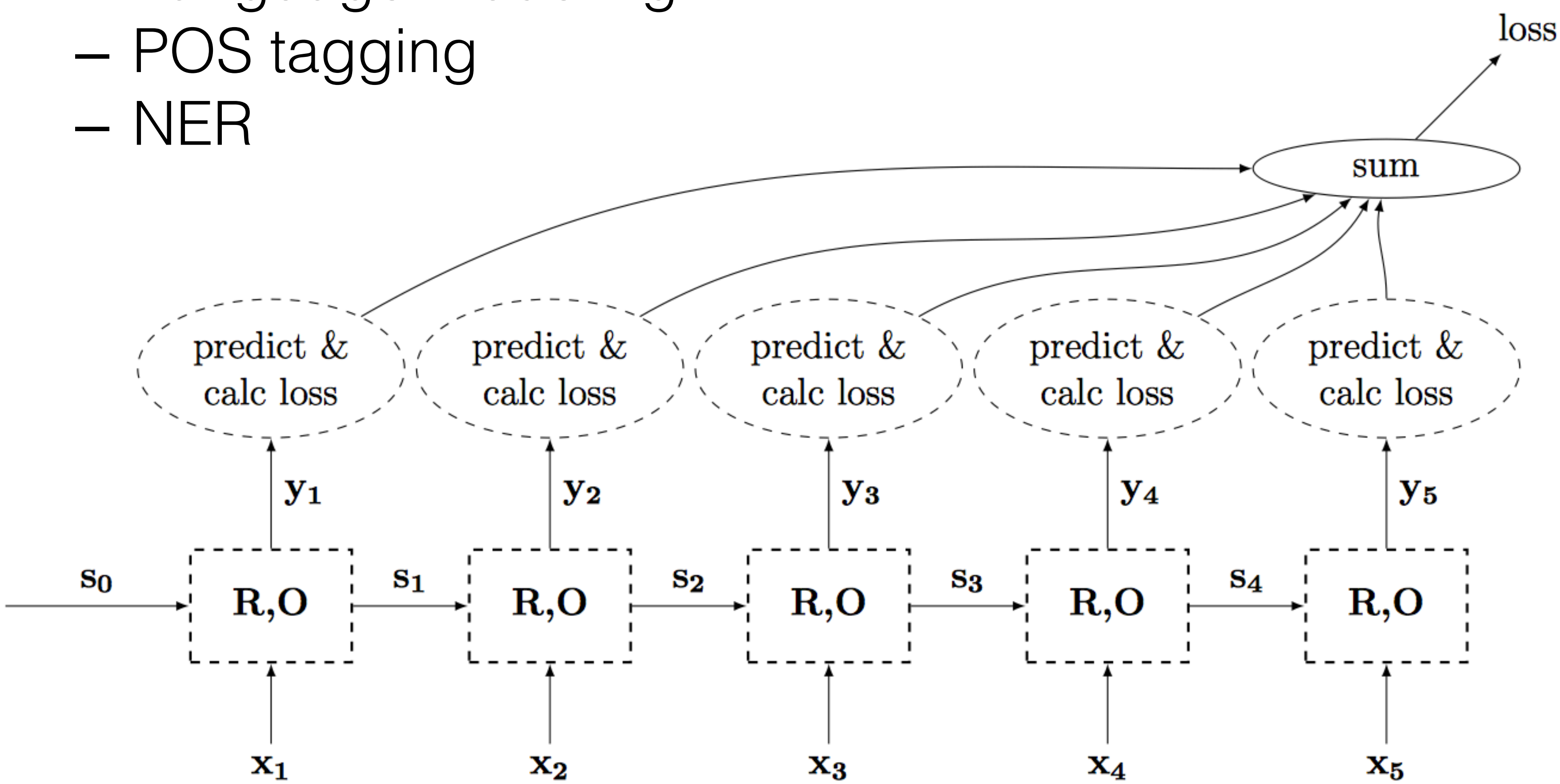
$$O(\boldsymbol{s}_i) = \mathrm{softmax}(s_i \boldsymbol{W} + \boldsymbol{b})$$

- Predict next token $\hat{y}_i$ as we go:

$$\hat{y}_i = \mathrm{argmax} O(\boldsymbol{s}_i)$$

RNN: Transducer Architecture

- Predict output for every time step
- Examples:
  - Language modeling
  - POS tagging
  - NER

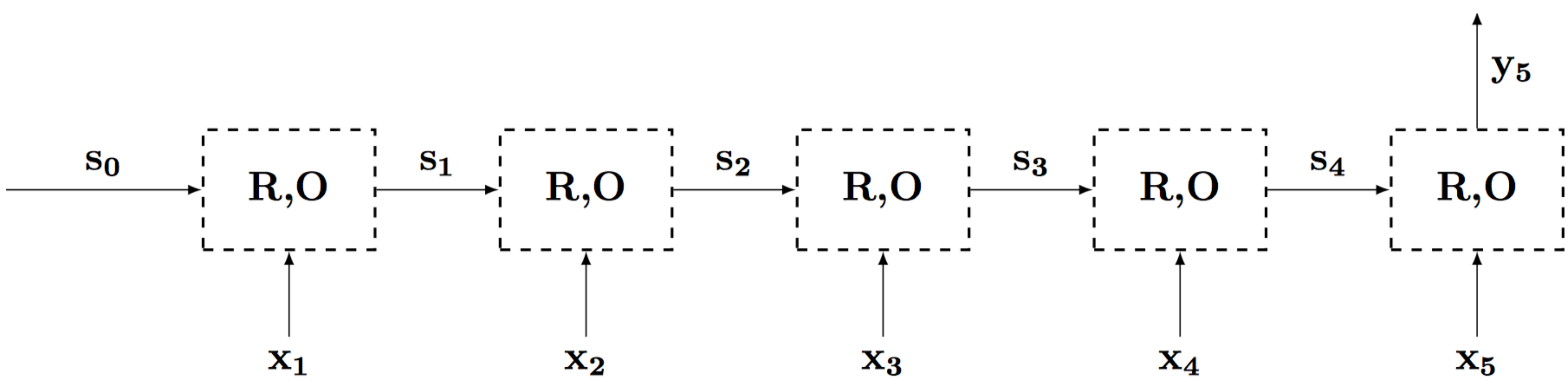


RNN: Encoder Architecture

- Similar to acceptor
- Difference: last state is used as input to another model and not for prediction

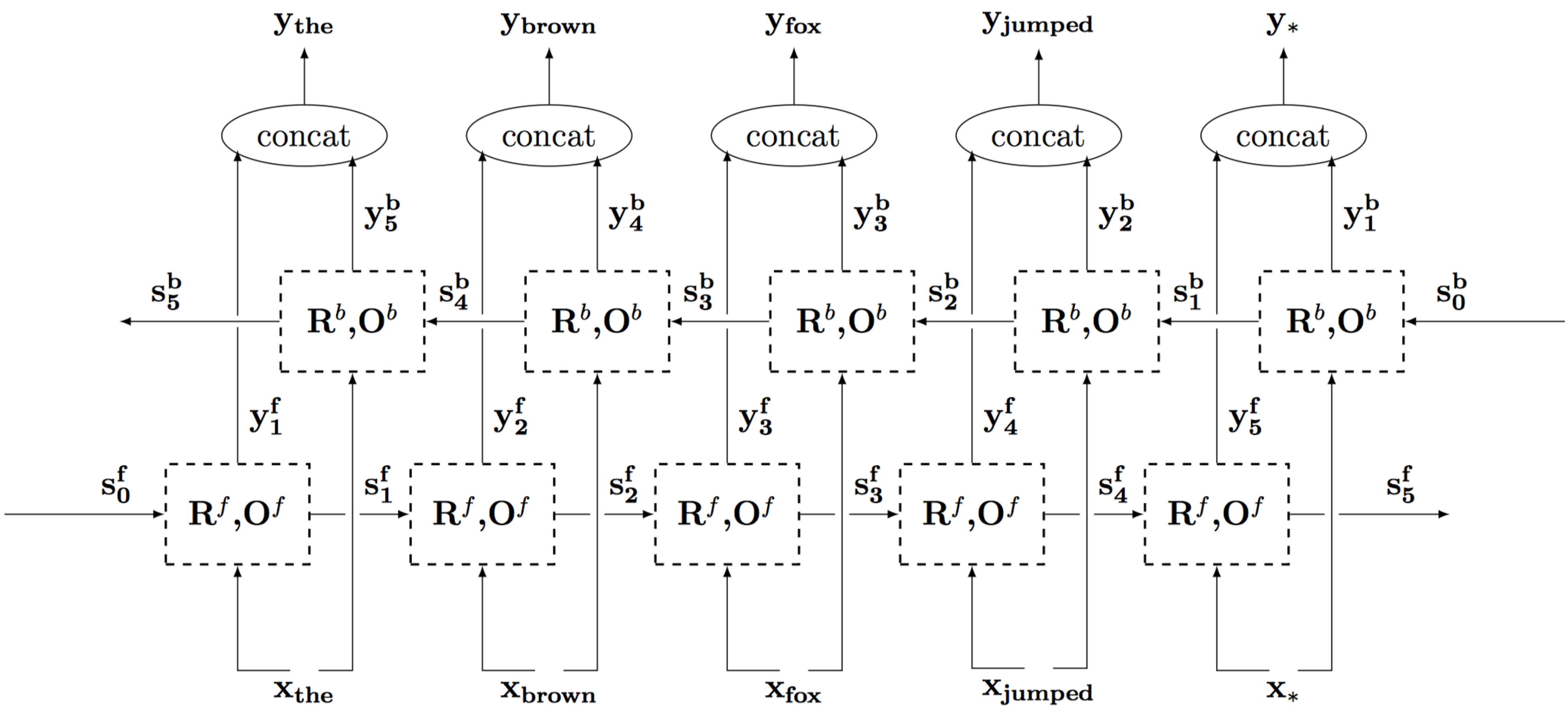
$$O(s_i) = s_i \rightarrow y_n = s_n$$

- Example:
  – Sentence embedding



Bidirectional RNNs

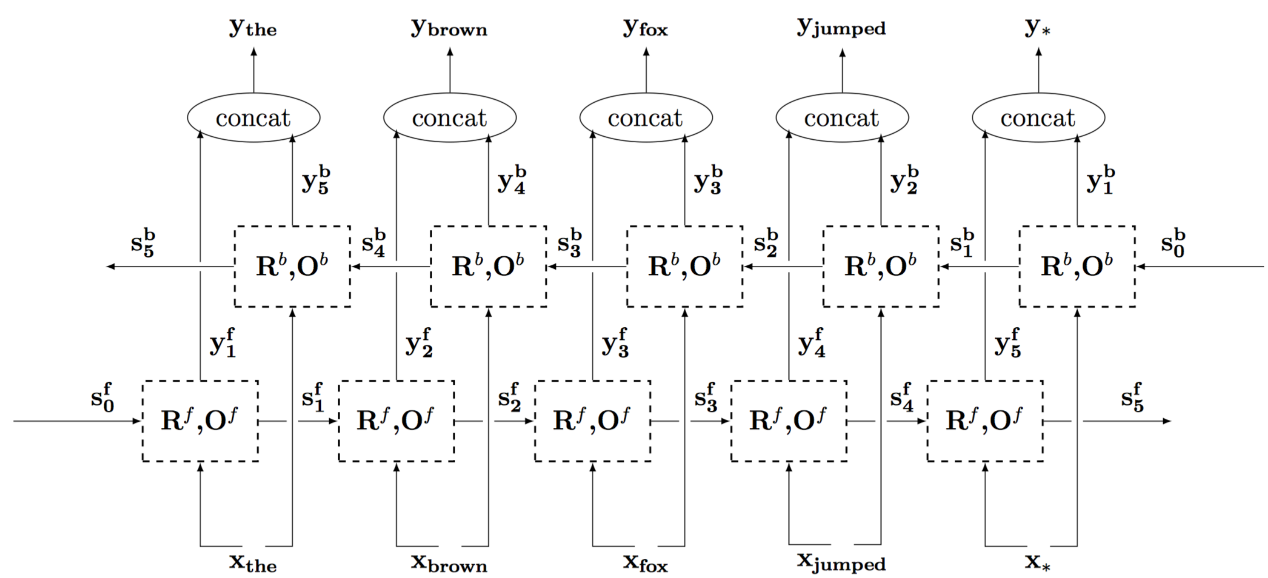
- RNN decisions are based on historical data only
  - How can we account for future input?
- When is it relevant? Feasible?



Bidirectional RNNs

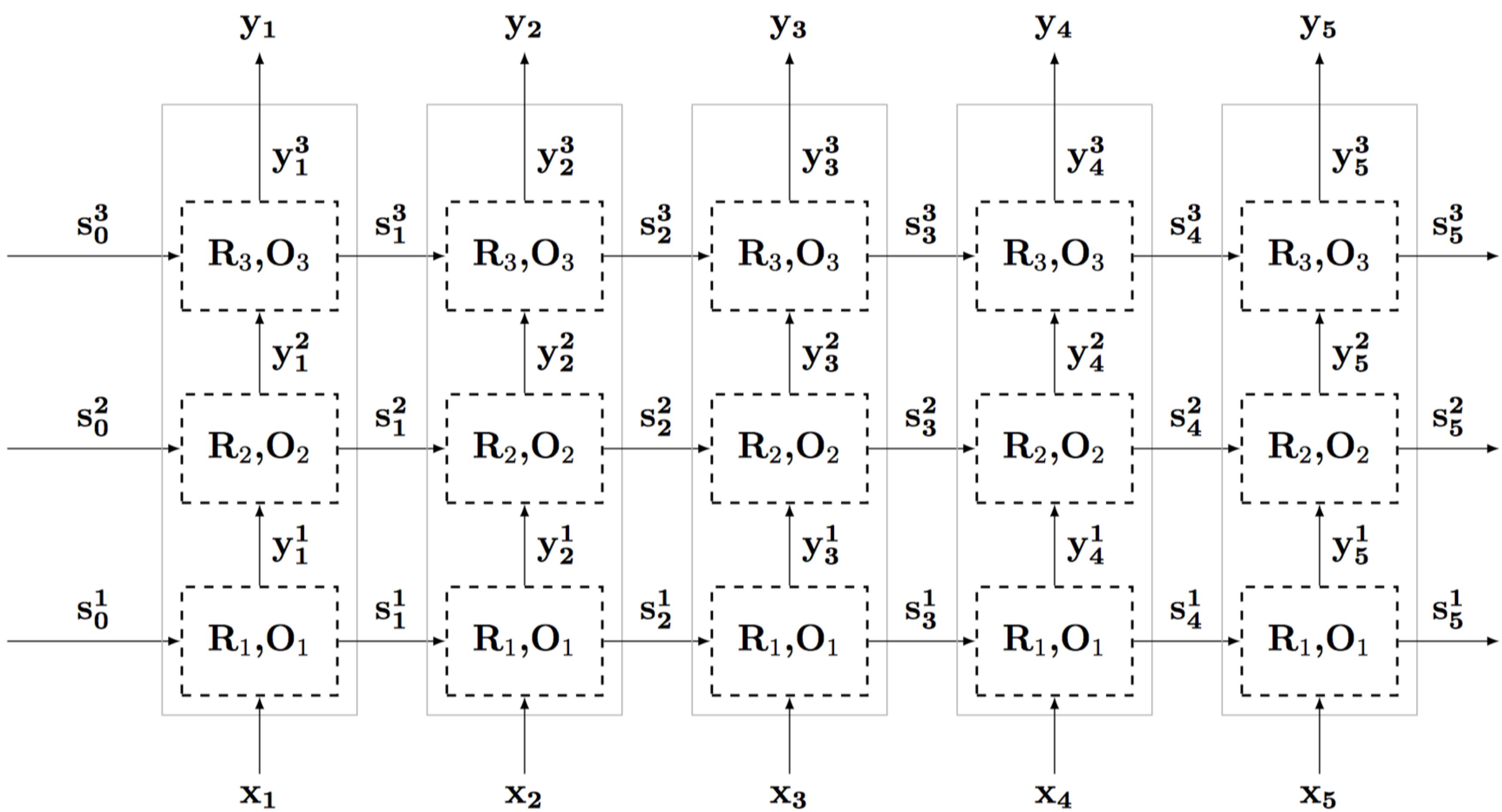
- RNN decisions are based on historical data only
  - How can we account for future input?
- When is it relevant? Feasible?
  - When all the input is possible. So not in real-time input, for example.
- Probabilistic model, for example for language modeling:

$$p(X) = \prod_{i=1}^{n} p(x_i \mid x_1, \dots, x_{i-1}, x_{i+1}, \dots, x_n)$$



Deep RNNs

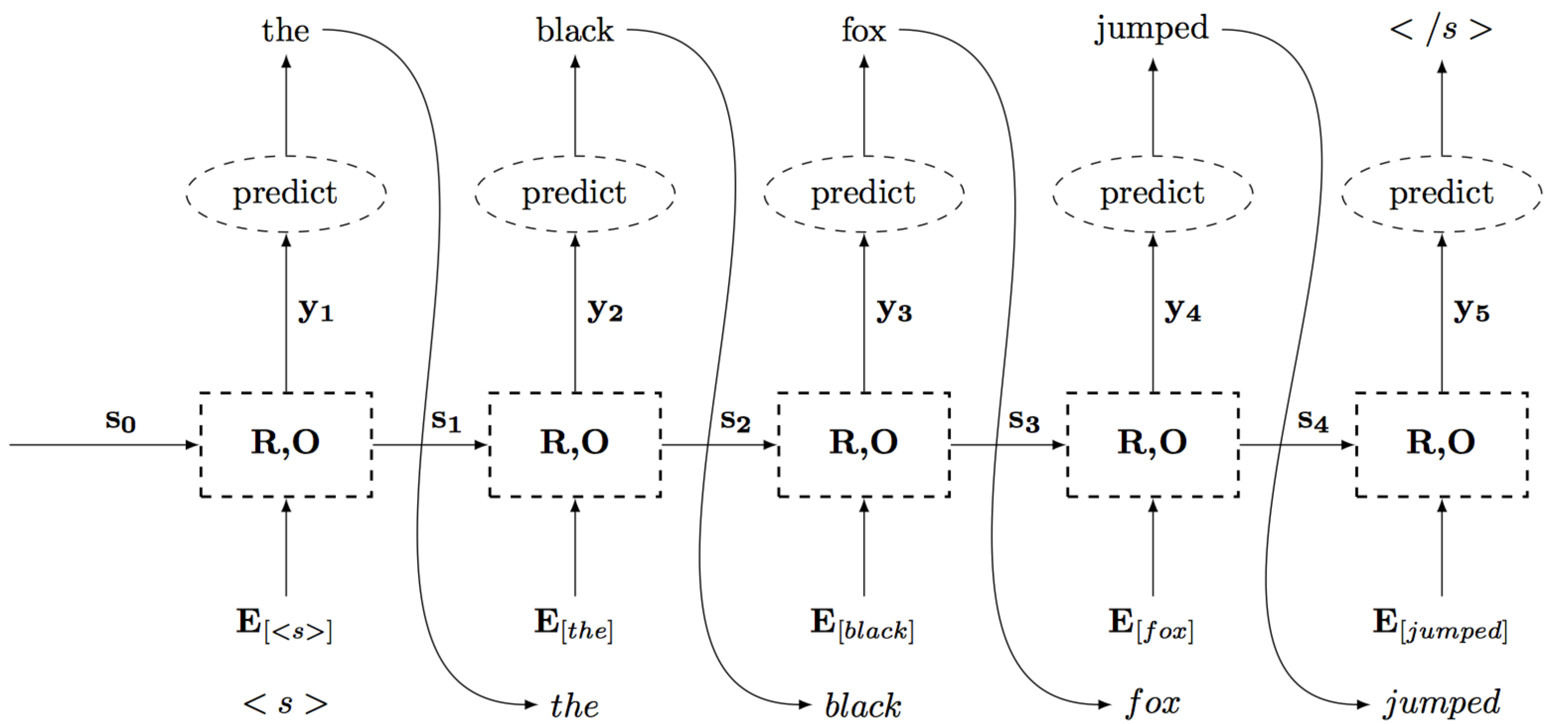
- Can also make RNNs deeper (vertically) to increase the model capacity



RNN: Generator

- Special case of the transducer architecture
- Generation conditioned on $\boldsymbol{s}_0$
- Probabilistic model:

$$p(X \mid s_0) = \prod_{i=1}^{n} p(x_i \mid x_1, \dots, x_{i-1}, s_0)$$



Example: Caption Generation

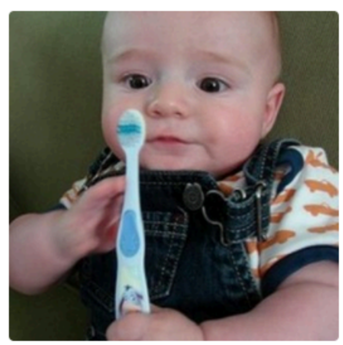
- Given: image I
- Goal: generate caption
- Set $\boldsymbol{s}_0 = \mathrm{CNN}(I)$
- Model:

$$p(X \mid I) = \prod_{i=1}^{n} p(x_i \mid x_1, \dots, x_{i-1}, I)$$

"little girl is eating piece of cake."

"baseball player is throwing ball in game."

"woman is holding bunch of bananas."



"a young boy is holding a baseball bat."

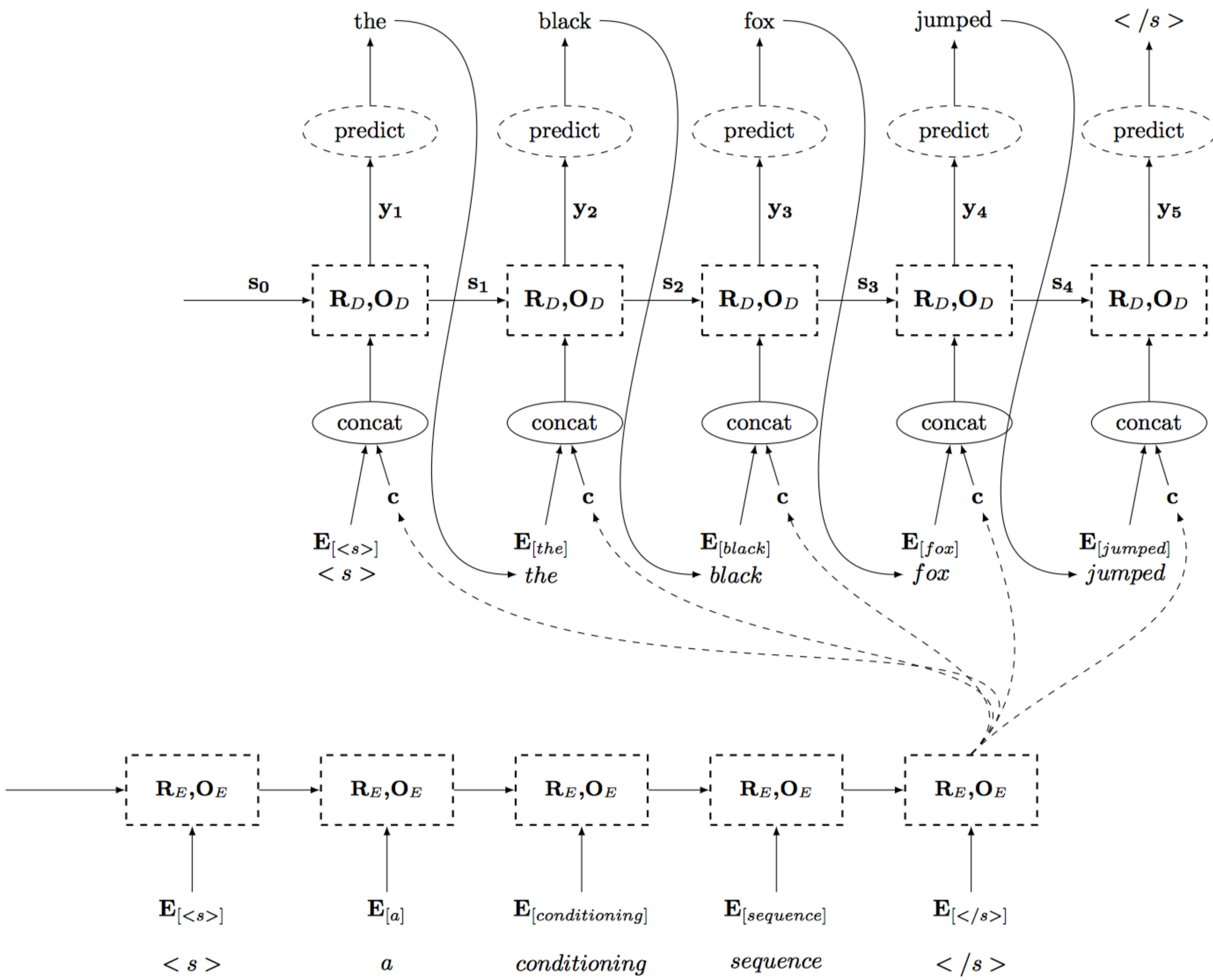
"a cat is sitting on a couch with a remote control."

"a woman holding a teddy bear in front of a mirror."

Examples from Karpathy and Fei-Fei 2015

Sequence-to-Sequence

- Connect encoder and generator
- Many alternatives:
  - Set generator $\boldsymbol{s}_0^d$ to encoder output $\boldsymbol{s}_n^e$
  - Concatenate generator $\boldsymbol{s}_0^d$ with each step input during generation
- Examples:
  - Machine translation
  - Chatbots
  - Dialog systems
- Can also generate other sequences – not only natural language!



Long-range Interactions

- Promise: Learn long-range interactions of language from data
- Example:

  How can you not see this movie?

  You should not see this movie.

- Sometimes: requires ”remembering” early state
  - Key signal here is at s_1, but gradient is at s_n

Long-term Gradients

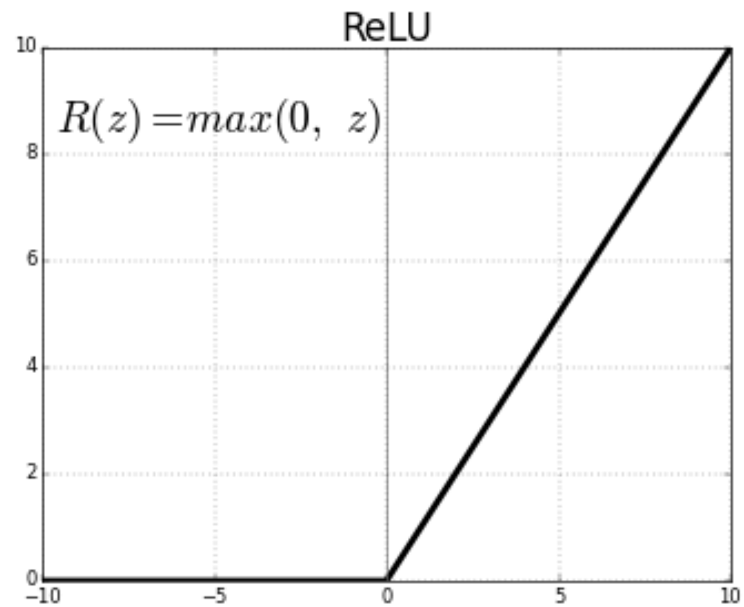
- Gradient go through (many) multiplications
- OK at end layers → close to the loss
- But: issue with early layers
- For example, derivative of $\tanh$

$$\frac{d}{dx}\tanh x = 1 - \tanh^2 x$$

  - Large activation → gradient disappears
- In other activation functions, values can become larger and larger

Exploding Gradients

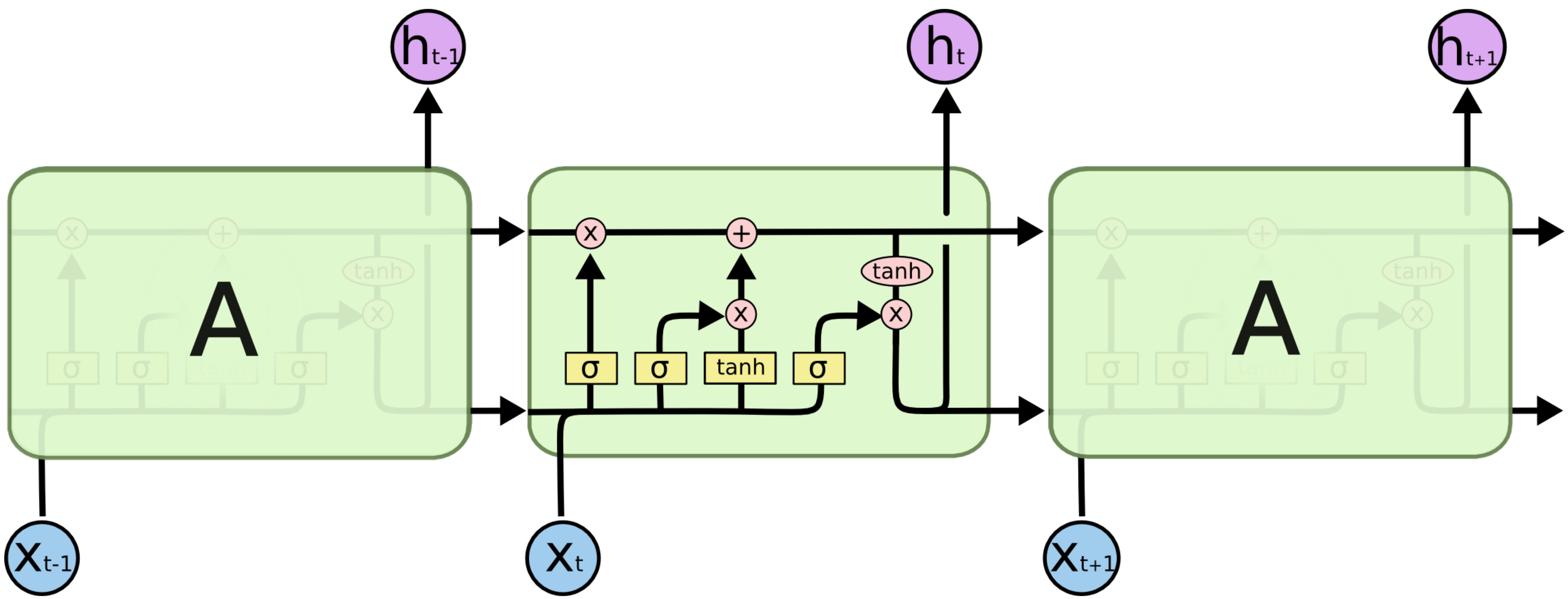
- Common when there is not saturation in activation (e.g., ReLu) and we get exponential blowup
- Result: reasonable short-term gradient, but bad long-term ones
- Common heuristic:
  - Gradient clipping: bounding all gradients by maximum value



Vanishing Gradients

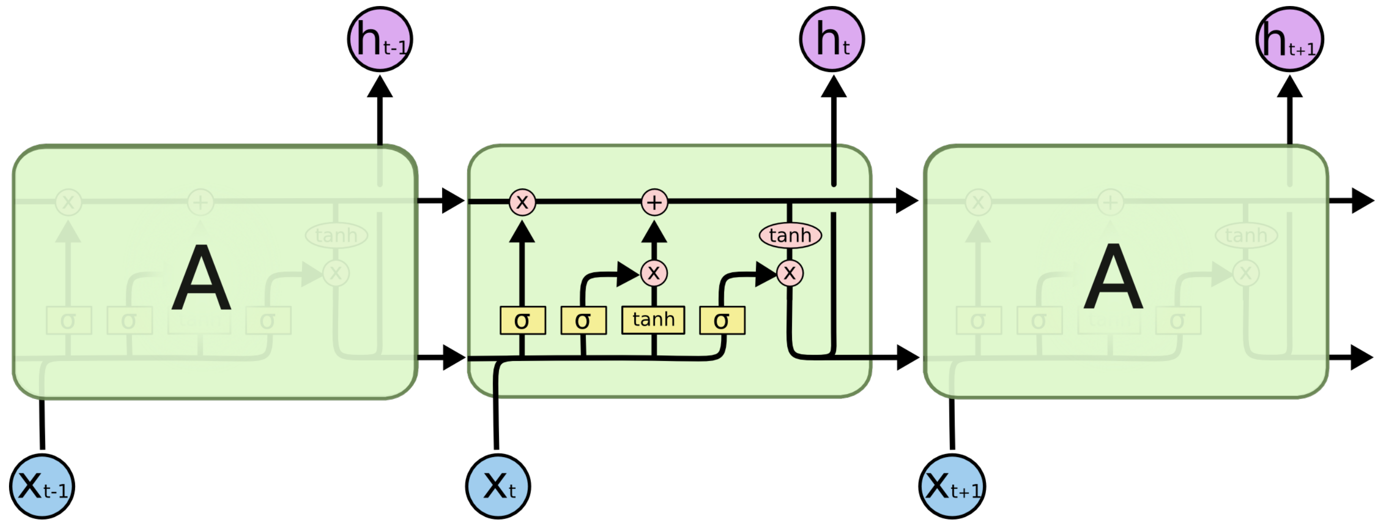
- Occurs when multiplying small values
  - For example: when $\tanh$ saturates
- Mainly affects long-term gradients
- Solving this is more complex

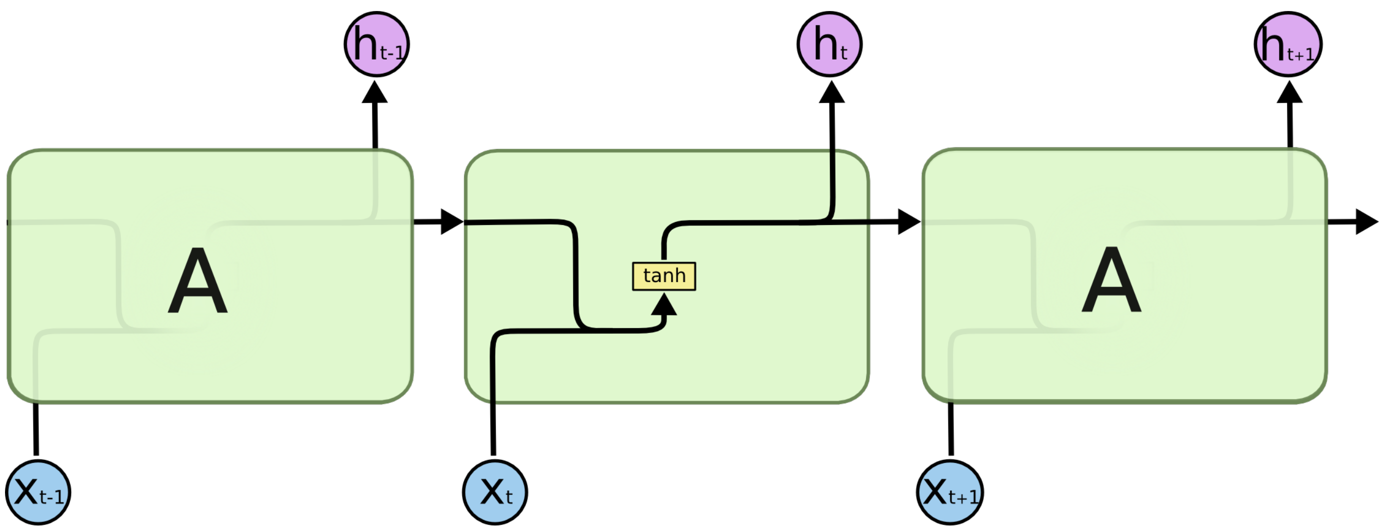
Long Short-term Memory (LSTM)



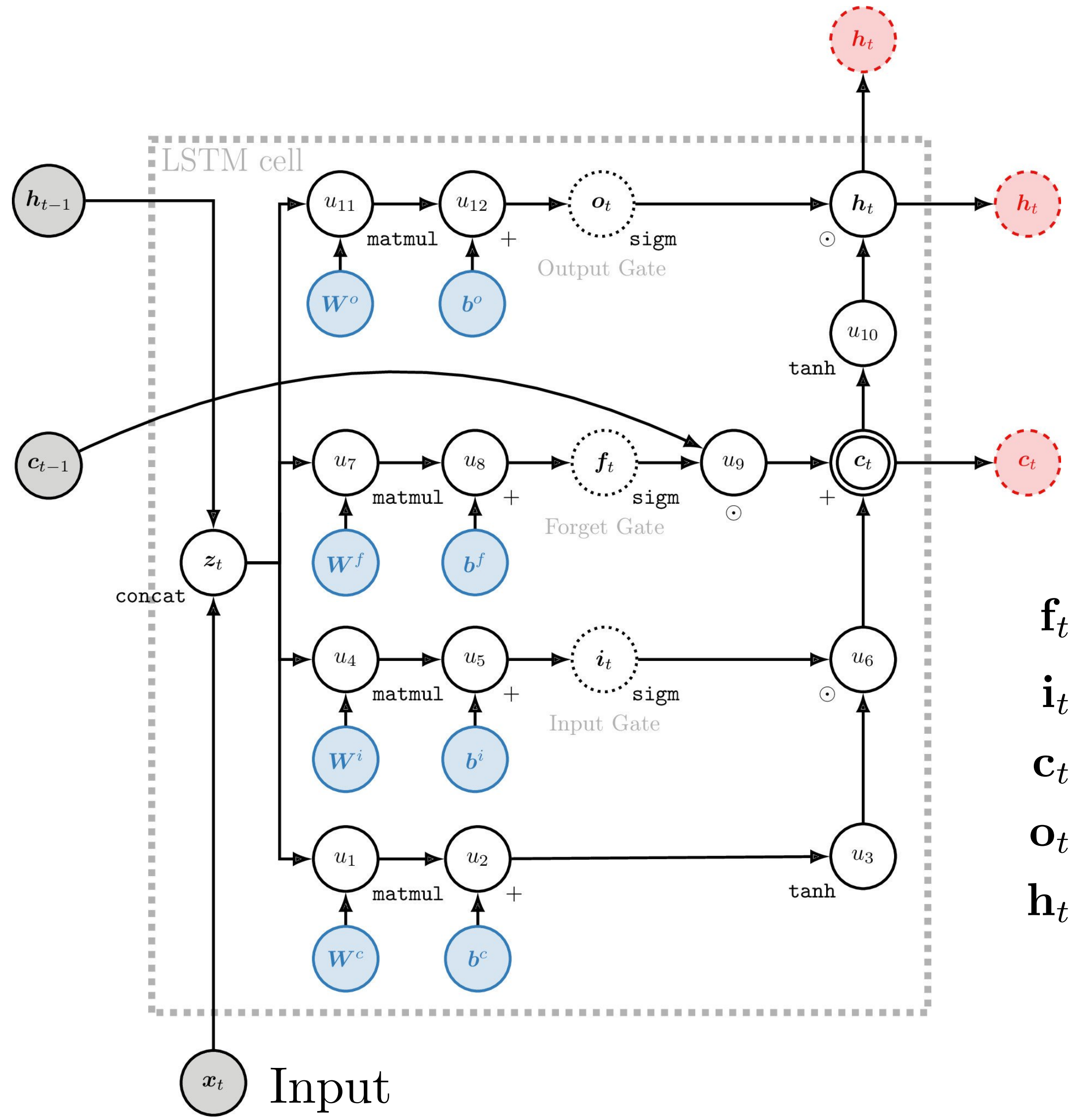
Hochreiter and Schmidhuber (1997)

LSTM vs. Elman RNN





LSTM



$$
\begin{aligned}
\mathbf{f}_t &= \sigma(\mathbf{W}^f[\mathbf{h}_{t-1}, \mathbf{x}_t] + \mathbf{b}^f) \\
\mathbf{i}_t &= \sigma(\mathbf{W}^i[\mathbf{h}_{t-1}, \mathbf{x}_i] + \mathbf{b}^f) \\
\mathbf{c}_t &= \mathbf{f}_t \odot \mathbf{c}_{t-1} + \mathbf{i}_t \odot \tanh(\mathbf{W}^c[\mathbf{h}_{t-1}, \mathbf{x}_i] + \mathbf{b}^c) \\
\mathbf{o}_t &= \sigma(\mathbf{W}^o[\mathbf{h}_{t-1}, \mathbf{x}_i] + \mathbf{b}^o) \\
\mathbf{h}_t &= \mathbf{o}_t \odot \tanh(\mathbf{c}_t)
\end{aligned}
$$

Image by Tim Rocktäschel