Invariance and Stability to Deformations of Deep Convolutional Representations

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This is in large parts the work of Alberto Bietti

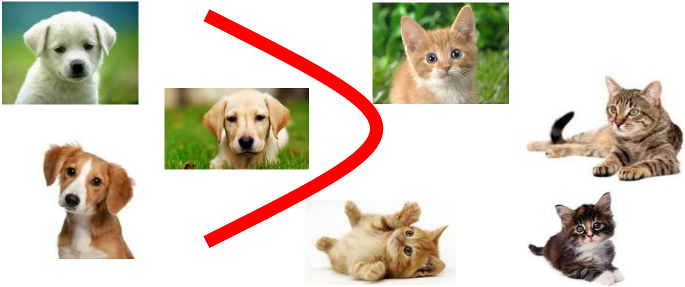
- A. Bietti and J. Mairal. Invariance and Stability of Deep Convolutional Representations. NIPS. 2017.
- A. Bietti and J. Mairal. **Group Invariance, Stability to Deformations, and Complexity of Deep Convolutional Representations.** JMLR. 2019.
- A. Bietti, G. Mialon, D. Chen, and J. Mairal. A Kernel Perspective for Regularizing Deep Neural Networks. arXiv. 2019.

Convolutional Neural Networks
Short Introduction and Current Challenges

Learning a predictive model

The goal is to learn a **prediction function** $f : \mathbb{R}^p \to \mathbb{R}$ given labeled training data $(x_i, y_i)_{i=1,\ldots,n}$ with x_i in $\mathbb{R}^p$, and y_i in $\mathbb{R}$:

$$\min_{f \in \mathcal{F}} \underbrace{\frac{1}{n}\sum_{i=1}^{n} L(y_i, f(x_i))}_{\text{empirical risk, data fit}} + \underbrace{\lambda\Omega(f)}_{\text{regularization}} .$$



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What is specific to multilayer neural networks?

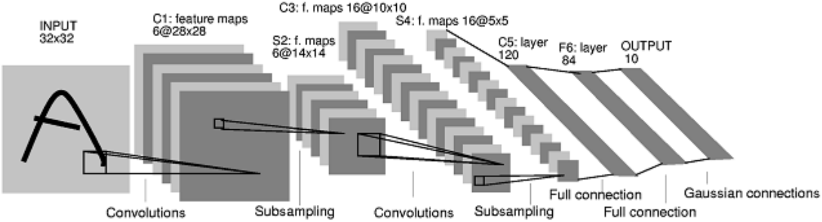
- The "neural network" space $\mathcal{F}$ is explicitly parametrized by:

$$f(x) = \sigma_k(W_k\sigma_{k-1}(W_{k-1}\ldots\sigma_2(W_2\sigma_1(W_1x))\ldots)).$$

- Linear operations are either unconstrained (fully connected) or share parameters (e.g., convolutions).
- Finding the optimal $W_1, W_2, \ldots, W_k$ yields a **non-convex** optimization problem in **huge dimension.**

Convolutional Neural Networks

Picture from LeCun et al. [1998]

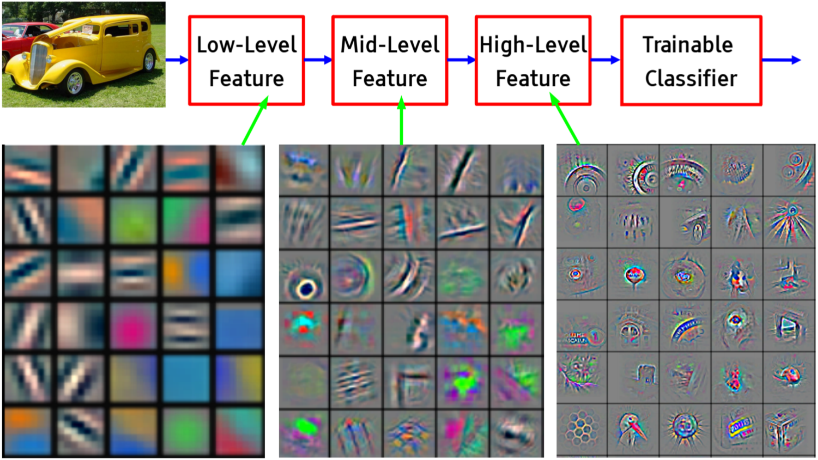


What are the main features of CNNs?

- they capture **compositional** and **multiscale** structures in images;
- they provide some **invariance**;
- they model **local stationarity** of images at several scales;
- they are **state-of-the-art** in many fields.

Convolutional Neural Networks

The keywords: **multi-scale, compositional, invariant, local features**.
Picture from Y. LeCun's tutorial:



Feature visualization of convolutional net trained on ImageNet from [Zeiler & Fergus 2013]

Convolutional Neural Networks

Picture from Olah et al. [2017]:

Edges (layer conv2d0) **Textures** (layer mixed3a) **Patterns** (layer mixed4a)

Convolutional Neural Networks

Picture from Olah et al. [2017]:

Patterns (layer mixed4a) **Parts** (layers mixed4b & mixed4c) **Objects** (layers mixed4d & mixed4e)

Convolutional Neural Networks: Challenges

What are current high-potential problems to solve?

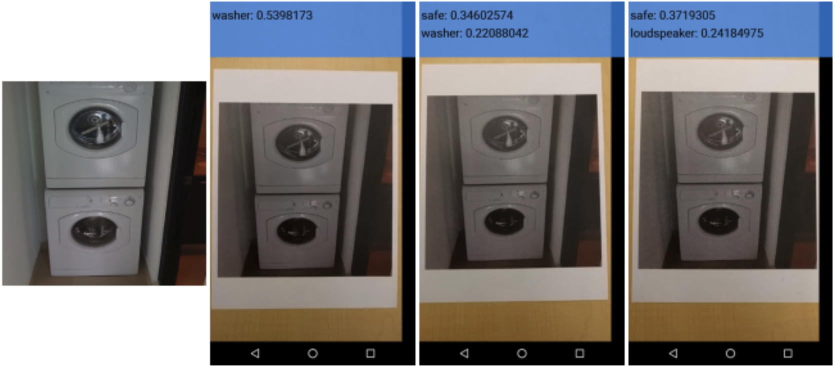
1. lack of **stability** (see next slide).
2. learning with **few labeled data**.
3. learning with **no supervision** (see Tab. from Bojanowski and Joulin, 2017).

Method	Acc@1
Random (Noroozi & Favaro, 2016)	12.0
SIFT+FV (Sánchez et al., 2013)	55.6
Wang & Gupta (2015)	29.8
Doersch et al. (2015)	30.4
Zhang et al. (2016)	35.2
[1]Noroozi & Favaro (2016)	38.1
BiGAN (Donahue et al., 2016)	32.2
NAT	36.0

Table 3. Comparison of the proposed approach to state-of-the-art unsupervised feature learning on ImageNet. A full multi-layer perceptron is retrained on top of the features. We compare to several self-supervised approaches and an unsupervised approach.

Convolutional Neural Networks: Challenges

Illustration of instability. Picture from Kurakin et al. [2016].



(a) Image from dataset (b) Clean image (c) Adv. image, $\epsilon = 4$ (d) Adv. image, $\epsilon = 8$

Figure: Adversarial examples are generated by computer; then printed on paper; a new picture taken on a smartphone fools the classifier.

Convolutional Neural Networks: Challenges

$$\min_{f\in\mathcal{F}} \underbrace{\frac{1}{n}\sum_{i=1}^{n} L(y_i, f(x_i))}_{\text{empirical risk, data fit}} + \underbrace{\lambda\Omega(f)}_{\text{regularization}}.$$

The issue of regularization

- today, heuristics are used (DropOut, weight decay, early stopping)...
- ...but they are not sufficient.
- how to **control variations of prediction functions**?

$$|f(x) - f(x')| \text{ should be close if } x \text{ and } x' \text{ are "similar".}$$

- what does it mean for x and x' to be "similar"?
- what should be a good **regularization function** Ω?

Invariance and Stability from a Kernel Perspective

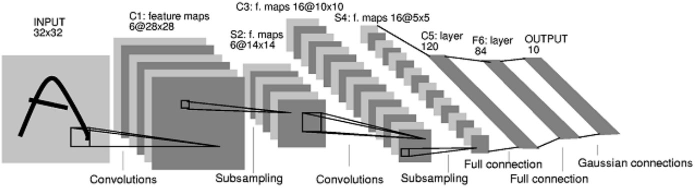
Objectives

Deep convolutional signal representations

- Are they **stable to deformations**?
- How can we achieve **invariance to transformation groups**?
- Do they **preserve signal information**?

Learning aspects

- Building a **functional space** for CNNs (or similar objects).
- Deriving a measure of **model complexity**.



A kernel perspective

Recipe

- Map data x to **high-dimensional space**, $\Phi(x)$ in $\mathcal{H}$ (RKHS), with Hilbertian geometry (projections, barycenters, angles, ..., exist!).
- predictive models f in $\mathcal{H}$ are **linear forms** in $\mathcal{H}$: $f(x) = \langle f, \Phi(x) \rangle_{\mathcal{H}}$.
- Learning with a positive definite kernel $K(x, x') = \langle \Phi(x), \Phi(x') \rangle_{\mathcal{H}}$.

[Schölkopf and Smola, 2002, Shawe-Taylor and Cristianini, 2004]...

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What is the relation with deep neural networks?

- It is possible to design a RKHS $\mathcal{H}$ where a large class of deep neural networks live [Mairal, 2016].

$$f(x) = \sigma_k(W_k \sigma_{k-1}(W_{k-1} \dots \sigma_2(W_2 \sigma_1(W_1 x)) \dots)) = \langle f, \Phi(x) \rangle_{\mathcal{H}}.$$

- This is the construction of "**convolutional kernel networks**".

[Schölkopf and Smola, 2002, Shawe-Taylor and Cristianini, 2004]...

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Why do we care?

- $\Phi(x)$ is related to the **network architecture** and is **independent of training data**. Is it stable? Does it lose signal information?
- f is a **predictive model**. Can we control its stability?

$$|f(x) - f(x')| \leq \|f\|_{\mathcal{H}} \|\Phi(x) - \Phi(x')\|_{\mathcal{H}}.$$

- $\|f\|_{\mathcal{H}}$ controls both **stability and generalization**!

A kernel perspective: digression about regularization

Assume we have an RKHS $\mathcal{H}$ for deep networks:

$$\min_{f \in \mathcal{H}} \frac{1}{n} \sum_{i=1}^{n} L(y_i, f(x_i)) + \frac{\lambda}{2} \|f\|_{\mathcal{H}}^2.$$

$\|.\|_{\mathcal{H}}$ encourages smoothness and stability w.r.t. the geometry induced by the kernel (which depends itself on the choice of architecture).

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Problem

Multilayer kernels developed for deep networks are **typically intractable**.

One solution [Mairal, 2016]

do kernel approximations at each layer, which lead to non-standard CNNs called convolutional kernel networks (CKNs).

A kernel perspective: digression about regularization

Another point of view: consider a classical CNN parametrized by θ, which live in the RKHS:

$$\min_{\theta \in \mathbb{R}^p} \frac{1}{n} \sum_{i=1}^{n} L(y_i, f_\theta(x_i)) + \frac{\lambda}{2} \|f_\theta\|_{\mathcal{H}}^2.$$

This is different than CKNs since f_θ admits a classical parametrization.

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Problem

$\|f_\theta\|_{\mathcal{H}}$ is **intractable**...

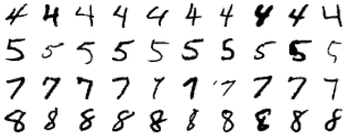
One solution [Bietti et al., 2019]

use approximations (lower- and upper-bounds), based on mathematical properties of $\|.\|_{\mathcal{H}}$.

A signal processing perspective

plus a bit of harmonic analysis

- consider images defined on a **continuous** domain $\Omega = \mathbb{R}^d$.
- $\tau : \Omega \to \Omega$: c^1-diffeomorphism.
- $L_\tau x(u) = x(u - \tau(u))$: action operator.
- much richer group of transformations than translations.



[Mallat, 2012, Allassonnière, Amit, and Trouvé, 2007, Trouvé and Younes, 2005]...

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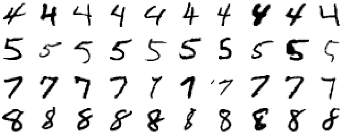

relation with deep convolutional representations

stability to deformations studied for wavelet-based scattering transform.

[Mallat, 2012, Bruna and Mallat, 2013, Sifre and Mallat, 2013]...

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Definition of stability

- Representation $\Phi(\cdot)$ is **stable** [Mallat, 2012] if:

$$\|\Phi(L_\tau x) - \Phi(x)\| \leq (C_1 \|\nabla \tau\|_\infty + C_2 \|\tau\|_\infty) \|x\|.$$

- $\|\nabla \tau\|_\infty = \sup_u \|\nabla \tau(u)\|$ controls deformation.
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Summary of our results

Multi-layer construction of the RKHS $\mathcal{H}$

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Signal representation

- **Signal preservation** of the multi-layer kernel mapping Φ.
- Conditions of **non-trivial stability** for Φ.
- Constructions to achieve **group invariance**.

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Multi-layer construction of the RKHS $\mathcal{H}$

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Signal representation

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On learning

- Bounds on the RKHS norm $\|.\|_{\mathcal{H}}$ to control **stability and generalization** of a predictive model f.

$$|f(x) - f(x')| \leq \|f\|_{\mathcal{H}} \|\Phi(x) - \Phi(x')\|_{\mathcal{H}}.$$

Outline

1. Construction of the multi-layer convolutional representation

2. Invariance and stability

3. Learning aspects: model complexity

A generic deep convolutional representation

Initial map x_0 in $L^2(\Omega, \mathcal{H}_0)$

$x_0 : \Omega \rightarrow \mathcal{H}_0$: **continuous** input signal

- $u \in \Omega = \mathbb{R}^d$: location (d = 2 for images).
- $x_0(u) \in \mathcal{H}_0$: input value at location u ($\mathcal{H}_0 = \mathbb{R}^3$ for RGB images).

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Building map x_k in $L^2(\Omega, \mathcal{H}_k)$ from x_{k-1} in $L^2(\Omega, \mathcal{H}_{k-1})$

$x_k : \Omega \to \mathcal{H}_k$: **feature map** at layer k

$$P_k x_{k-1}.$$

- P_k: **patch extraction** operator, extract small patch of feature map x_{k-1} around each point u ($P_k x_{k-1}(u)$ is a patch centered at u).

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$$x_k = A_k M_k P_k x_{k-1}.$$

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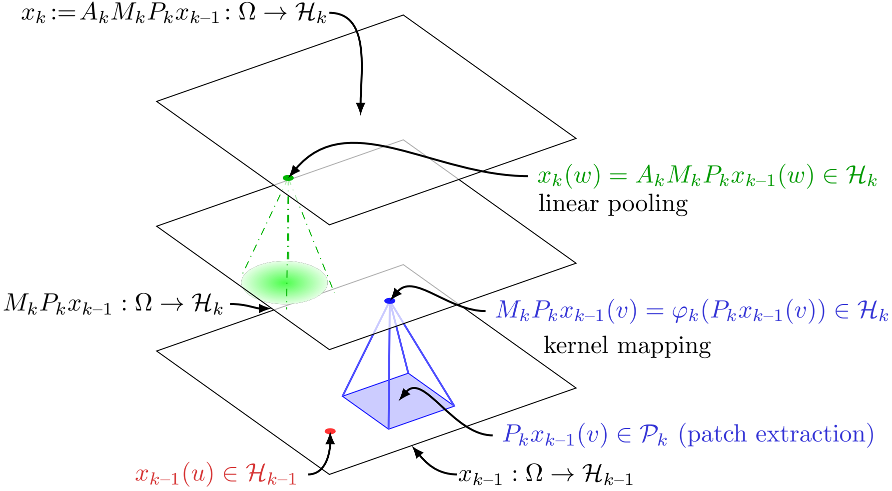
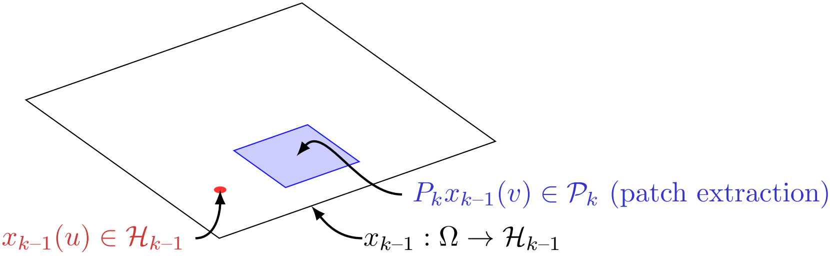
- A_k: (linear) **pooling** operator at scale σ_k.

A generic deep convolutional representation



Patch extraction operator P_k

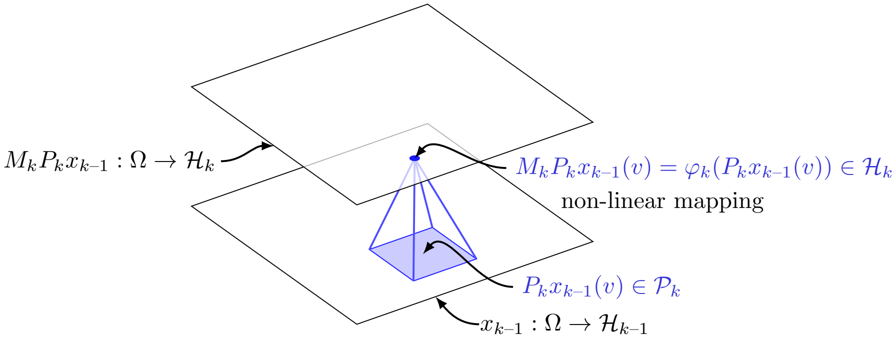
$$P_k x_{k-1}(u) := (v \in S_k \mapsto x_{k-1}(u+v)) \in \mathcal{P}_k = \mathcal{H}_{k-1}^{S_k}.$$



- S_k: patch shape, e.g. box.
- P_k is **linear**, and **preserves the norm**: $\|P_k x_{k-1}\| = \|x_{k-1}\|$.
- Norm of a map: $\|x\|^2 = \int_\Omega \|x(u)\|^2 du < \infty$ for x in $L^2(\Omega, \mathcal{H})$.

Non-linear pointwise mapping operator M_k

$$M_k P_k x_{k-1}(u) := \varphi_k(P_k x_{k-1}(u)) \in \mathcal{H}_k.$$



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- $\varphi_k : \mathcal{P}_k \to \mathcal{H}_k$ pointwise non-linearity on patches.
- We assume **non-expansivity**

$$\|\varphi_k(z)\| \leq \|z\| \quad \text{and} \quad \|\varphi_k(z) - \varphi_k(z')\| \leq \|z - z'\|.$$

- M_k then satisfies, for $x, x' \in L^2(\Omega, \mathcal{P}_k)$

$$\|M_k x\| \leq \|x\| \quad \text{and} \quad \|M_k x - M_k x'\| \leq \|x - x'\|.$$

φ_k from kernels

- Kernel mapping of **homogeneous dot-product kernels**:

$$K_k(z, z') = \|z\|\|z'\|\kappa_k\left(\frac{\langle z, z'\rangle}{\|z\|\|z'\|}\right) = \langle \varphi_k(z), \varphi_k(z')\rangle.$$

- $\kappa_k(u) = \sum_{j=0}^{\infty} b_j u^j$ with $b_j \geq 0$, $\kappa_k(1) = 1$.
- $\|\varphi_k(z)\| = K_k(z, z)^{1/2} = \|z\|$ (**norm preservation**).
- $\|\varphi_k(z) - \varphi_k(z')\| \leq \|z - z'\|$ if $\kappa_k'(1) \leq 1$ (**non-expansiveness**).

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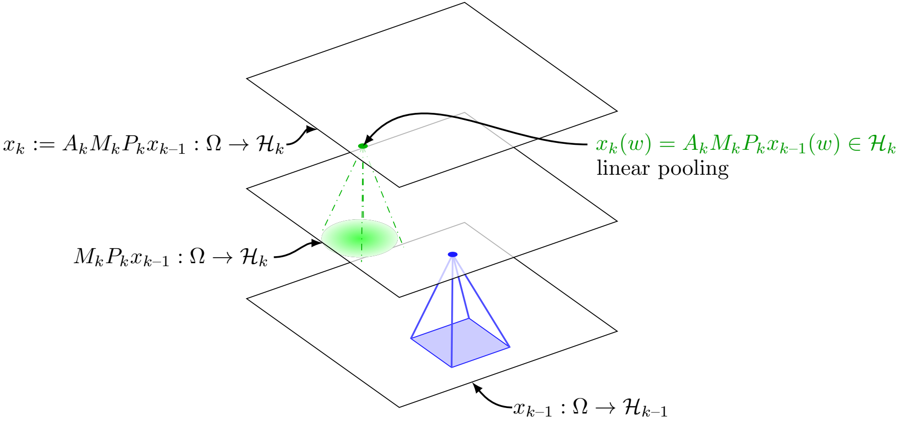
Examples

- $\kappa_{\text{exp}}(\langle z, z'\rangle) = e^{\langle z, z'\rangle - 1} = e^{-\frac{1}{2}\|z - z'\|^2}$ (if $\|z\| = \|z'\| = 1$).
- $\kappa_{\text{inv-poly}}(\langle z, z'\rangle) = \frac{1}{2 - \langle z, z'\rangle}$.

[Schoenberg, 1942, Scholkopf, 1997, Smola et al., 2001, Cho and Saul, 2010, Zhang et al., 2016, 2017, Daniely et al., 2016, Bach, 2017, Mairal, 2016]...

Pooling operator A_k

$$x_k(u) = A_k M_k P_k x_{k-1}(u) = \int_{\mathbb{R}^d} h_{\sigma_k}(u-v) M_k P_k x_{k-1}(v) dv \in \mathcal{H}_k.$$



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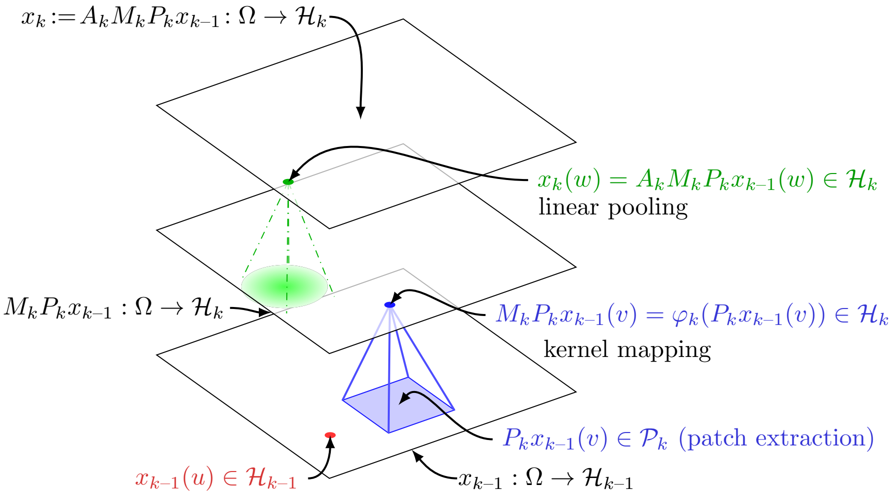
- h_{σ_k}: pooling filter at scale σ_k.
- $h_{\sigma_k}(u) := \sigma_k^{-d} h(u/\sigma_k)$ with $h(u)$ **Gaussian**.
- **linear, non-expansive operator**: $\|A_k\| \leq 1$ (operator norm).

Recap: P_k, M_k, A_k



Multilayer construction

Assumption on x_0

- x_0 is typically a **discrete** signal aquired with physical device.
- Natural assumption: $x_0 = A_0 x$, with x the original continuous signal, A_0 local integrator with scale σ_0 (**anti-aliasing**).

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Multilayer representation

$$\Phi_n(x) = A_n M_n P_n A_{n-1} M_{n-1} P_{n-1} \cdots A_1 M_1 P_1 x_0 \;\in\; L^2(\Omega, \mathcal{H}_n).$$

- S_k, σ_k grow exponentially in practice (i.e., fixed with subsampling).

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Prediction layer

- e.g., linear $f(x) = \langle w, \Phi_n(x) \rangle$.
- "linear kernel" $\mathcal{K}(x, x') = \langle \Phi_n(x), \Phi_n(x') \rangle = \int_\Omega \langle x_n(u), x'_n(u) \rangle du$.

Outline

Invariance, definitions

- $\tau : \Omega \to \Omega$: C^1-diffeomorphism with $\Omega = \mathbb{R}^d$.
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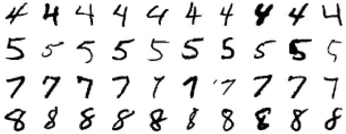

[Mallat, 2012, Bruna and Mallat, 2013, Sifre and Mallat, 2013]...

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Warmup: translation invariance

Representation

$$\Phi_n(x) \stackrel{\triangle}{=} A_n M_n P_n A_{n-1} M_{n-1} P_{n-1} \cdots A_1 M_1 P_1 A_0 x.$$

How to achieve translation invariance?

- Translation: $L_c x(u) = x(u - c)$.

Warmup: translation invariance

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- *Equivariance* - all operators commute with L_c: $\Box L_c = L_c \Box$.

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\|\Phi_n(L_c x) - \Phi_n(x)\| &= \|L_c \Phi_n(x) - \Phi_n(x)\| \\
&\leq \|L_c A_n - A_n\| \cdot \|M_n P_n \Phi_{n-1}(x)\| \\
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\end{aligned}$$

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- Mallat [2012]: $\|L_\tau A_n - A_n\| \leq \frac{C_2}{\sigma_n} \|\tau\|_\infty$ (operator norm).

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- **Scale σ_n of the last layer controls translation invariance.**

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- Adapt to **current layer resolution**, patch size controlled by σ_{k-1}:

$$\|[P_k A_{k-1}, L_\tau]\| \leq C_{1,\kappa} \|\nabla \tau\|_\infty \qquad \sup_{u \in S_k} |u| \leq \kappa \sigma_{k-1}$$

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- $C_{1,\kappa}$ grows as $\kappa^{d+1} \implies$ more stable with **small patches** (e.g., 3x3, VGG et al.).

Stability to deformations: final result

Theorem

If $\|\nabla\tau\|_\infty \leq 1/2$,

$$\|\Phi_n(L_\tau x) - \Phi_n(x)\| \leq \left(C_{1,\kappa}\,(n+1)\,\|\nabla\tau\|_\infty + \frac{C_2}{\sigma_n}\|\tau\|_\infty\right)\|x\|.$$

- translation invariance: large σ_n.
- stability: small patch sizes.
- signal preservation: subsampling factor $\approx$ patch size.
- $\Longrightarrow$ **needs several layers.**

related work on stability [Wiatowski and Bölcskei, 2017]

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- signal preservation: subsampling factor $\approx$ patch size.
- $\Longrightarrow$ **needs several layers.**
- requires additional discussion to make stability non-trivial.

related work on stability [Wiatowski and Bölcskei, 2017]

Beyond the translation group

Can we achieve invariance to other groups?

- Group action: $L_g x(u) = x(g^{-1}u)$ (e.g., rotations, reflections).
- Feature maps $x(u)$ defined on $u \in G$ (G: locally compact group).

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Recipe: Equivariant inner layers + global pooling in last layer

- **Patch extraction**:

$$Px(u) = (x(uv))_{v \in S}.$$

- **Non-linear mapping**: equivariant because pointwise!
- **Pooling** (μ: left-invariant Haar measure):

$$Ax(u) = \int_G x(uv)h(v)d\mu(v) = \int_G x(v)h(u^{-1}v)d\mu(v).$$

related work [Sifre and Mallat, 2013, Cohen and Welling, 2016, Raj et al., 2016]...

Group invariance and stability

Previous construction is similar to Cohen and Welling [2016] for CNNs.

A case of interest: the roto-translation group

- $G = \mathbb{R}^2 \rtimes SO(2)$ (mix of translations and rotations).
- **Stability** with respect to the translation group.
- **Global invariance** to rotations (only global pooling at final layer).
  - Inner layers: only pool on translation group.
  - Last layer: global pooling on rotations.
  - Cohen and Welling [2016]: pooling on rotations in inner layers hurts performance on Rotated MNIST

Discretization and signal preservation: example in 1D

- Discrete signal $\bar{x_k}$ in $\ell^2(\mathbb{Z}, \bar{\mathcal{H}_k})$ vs continuous ones x_k in $L^2(\mathbb{R}, \mathcal{H}_k)$.
- $\bar{x}_k$: subsampling factor s_k after pooling with scale $\sigma_k \approx s_k$:

$$\bar{x}_k[n] = \bar{A}_k \bar{M}_k \bar{P}_k \bar{x}_{k-1}[n s_k].$$

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- How? Recover patches with **linear functions** (contained in $\bar{\mathcal{H}}_k$)

$$\langle f_w, \bar{M}_k \bar{P}_k \bar{x}_{k-1}(u) \rangle = f_w(\bar{P}_k \bar{x}_{k-1}(u)) = \langle w, \bar{P}_k \bar{x}_{k-1}(u) \rangle,$$

and

$$\bar{P}_k \bar{x}_{k-1}(u) = \sum_{w \in B} \langle f_w, \bar{M}_k \bar{P}_k \bar{x}_{k-1}(u) \rangle w.$$

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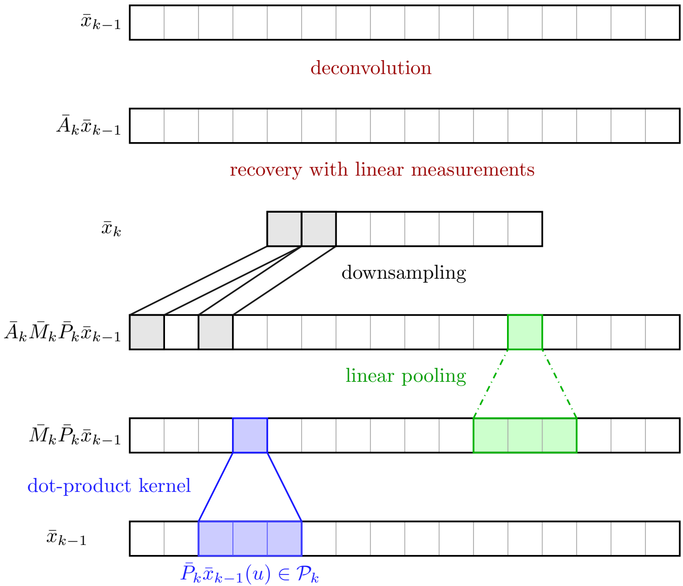
Warning: no claim that recovery is practical and/or stable.

Discretization and signal preservation: example in 1D



Outline

RKHS of patch kernels K_k

$$K_k(z, z') = \|z\|\|z'\|\kappa\left(\frac{\langle z, z'\rangle}{\|z\|\|z'\|}\right), \qquad \kappa(u) = \sum_{j=0}^{\infty} b_j u^j.$$

What does the RKHS contain?

Homogeneous version of [Zhang et al., 2016, 2017]

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What does the RKHS contain?

- RKHS contains **homogeneous functions**:

$$f : z \mapsto \|z\|\sigma(\langle g, z\rangle / \|z\|).$$

Homogeneous version of [Zhang et al., 2016, 2017]

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$$f : z \mapsto \|z\|\sigma(\langle g, z\rangle/\|z\|).$$

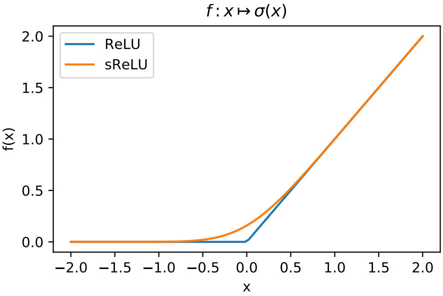
- **Smooth activations**: $\sigma(u) = \sum_{j=0}^{\infty} a_j u^j$ with $a_j \geq 0$.
- Norm: $\|f\|_{\mathcal{H}_k}^2 \leq C_\sigma^2(\|g\|^2) = \sum_{j=0}^{\infty} \frac{a_j^2}{b_j}\|g\|^2 < \infty$.

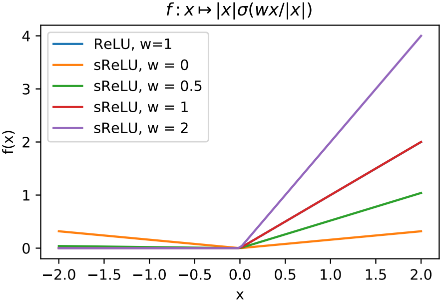
Homogeneous version of [Zhang et al., 2016, 2017]

RKHS of patch kernels K_k

Examples:

- $\sigma(u) = u$ (linear): $C_\sigma^2(\lambda^2) = O(\lambda^2)$.
- $\sigma(u) = u^p$ (polynomial): $C_\sigma^2(\lambda^2) = O(\lambda^{2p})$.
- $\sigma \approx$ sin, sigmoid, smooth ReLU: $C_\sigma^2(\lambda^2) = O(e^{c\lambda^2})$.





Constructing a CNN in the RKHS $\mathcal{H}_{\mathcal{K}}$

Some CNNs live in the RKHS: "linearization" principle

$$f(x) = \sigma_k(W_k \sigma_{k-1}(W_{k-1} \ldots \sigma_2(W_2 \sigma_1(W_1 x)) \ldots)) = \langle f, \Phi(x) \rangle_{\mathcal{H}}.$$

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- Consider a CNN with filters $W_k^{ij}(u), u \in S_k$.
  - k: layer;
  - i: index of filter;
  - j: index of input channel.
- "Smooth homogeneous" activations σ.
- The CNN can be constructed hierarchically in $\mathcal{H}_\mathcal{K}$.
- Norm (linear layers):

$$\|f_\sigma\|^2 \leq \|W_{n+1}\|_2^2 \cdot \|W_n\|_2^2 \cdot \|W_{n-1}\|_2^2 \ldots \|W_1\|_2^2.$$

- Linear layers: product of spectral norms.

Link with generalization

Direct application of classical generalization bounds

- Simple bound on Rademacher complexity for linear/kernel methods:

$$\mathcal{F}_B = \{f \in \mathcal{H}_{\mathcal{K}}, \|f\| \leq B\} \implies \mathsf{Rad}_N(\mathcal{F}_B) \leq O\left(\frac{BR}{\sqrt{N}}\right).$$

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- Leads to margin bound $O(\|\hat{f}_N\|R/\gamma\sqrt{N})$ for a learned CNN $\hat{f}_N$ with margin (confidence) $\gamma > 0$.
- Related to recent generalization bounds for neural networks based on **product of spectral norms** [e.g., Bartlett et al., 2017, Neyshabur et al., 2018].

[see, e.g., Boucheron et al., 2005, Shalev-Shwartz and Ben-David, 2014]...

Deep convolutional representations: conclusions

Study of generic properties of signal representation

- **Deformation stability** with small patches, adapted to resolution.
- **Signal preservation** when subsampling $\leq$ patch size.
- **Group invariance** by changing patch extraction and pooling.

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Applies to learned models

- Same quantity $\|f\|$ controls stability and generalization.
- "higher capacity" is needed to discriminate small deformations.

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Questions:

- Better regularization?
- How does SGD control capacity in CNNs?
- What about networks with no pooling layers? ResNet?

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φ_k from kernel approximations: CKNs [Mairal, 2016]

- Approximate $\varphi_k(z)$ by **projection** (Nyström approximation) on

$$\mathcal{F} = \mathsf{Span}(\varphi_k(z_1), \ldots, \varphi_k(z_p)).$$

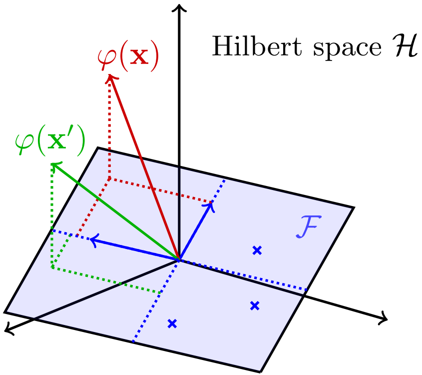

Figure: Nyström approximation.

[Williams and Seeger, 2001, Smola and Schölkopf, 2000, Zhang et al., 2008]...

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$$\mathcal{F} = \mathsf{Span}(\varphi_k(z_1), \ldots, \varphi_k(z_p)).$$

- Leads to **tractable**, p-dimensional representation $\psi_k(z)$.
- Norm is preserved, and projection is **non-expansive**:

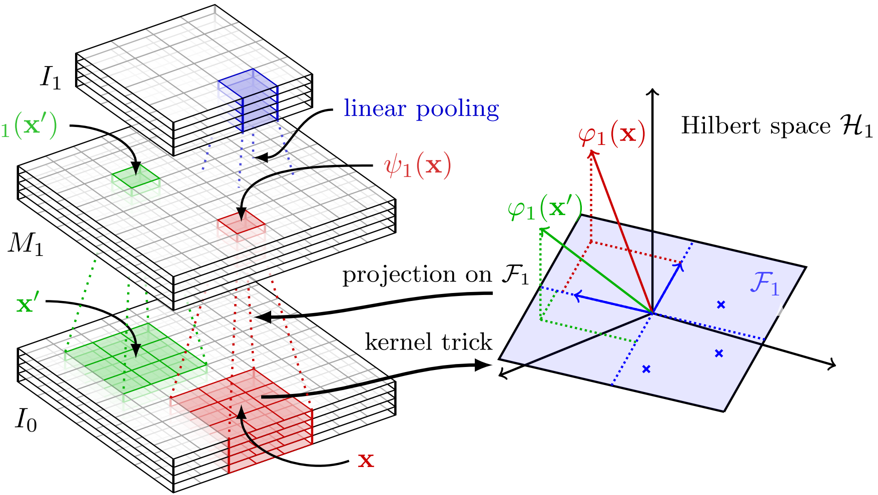
$$\begin{aligned} \|\psi_k(z) - \psi_k(z')\| &= \|\Pi_k \varphi_k(z) - \Pi_k \varphi_k(z')\| \\ &\leq \|\varphi_k(z) - \varphi_k(z')\| \leq \|z - z'\|. \end{aligned}$$

- Anchor points $z_1, \ldots, z_p$ ($\approx$ filters) can be **learned from data** (K-means or backprop).

[Williams and Seeger, 2001, Smola and Schölkopf, 2000, Zhang et al., 2008]...

φ_k from kernel approximations: CKNs [Mairal, 2016]

Convolutional kernel networks in practice.



Discussion

- norm of $\|\Phi(x)\|$ is of the same order (or close enough) to $\|x\|$.
- the kernel representation is non-expansive but not contractive

$$\sup_{x,x' \in L^2(\Omega,\mathcal{H}_0)} \frac{\|\Phi(x) - \Phi(x')\|}{\|x - x'\|} = 1.$$

A kernel perspective: digression about regularization

Another point of view: consider a classical CNN parametrized by θ, which live in the RKHS:

$$\min_{\theta \in \mathbb{R}^p} \frac{1}{n} \sum_{i=1}^{n} L(y_i, f_\theta(x_i)) + \frac{\lambda}{2} \|f_\theta\|_{\mathcal{H}}^2.$$

Upper-bounds

$$\|f\|_{\mathcal{H}} \leq \omega(\|A_k\|, \|A_k{-}1\|, \ldots, \|A_1\|) \quad \text{(spectral norms)}\ .$$

Lower-bounds

$$\|f\|_{\mathcal{H}} = \sup_{\|u\|_{\mathcal{H}} \leq 1} \langle f, u \rangle_{\mathcal{H}} \quad \geq \quad \sup_{u \in U} \langle f, u \rangle_{\mathcal{H}} \quad \text{for} \quad U \subseteq B_{\mathcal{H}}(1).$$

A kernel perspective: digression about regularization

- adversarial penalty

$$U = \{\Phi(x+\delta) - \Phi(x) : x \in \mathcal{X}, \|\delta\|_2 \leq 1\}$$
$$\Rightarrow \|f\|_\delta^2 = \sup_{x \in \mathcal{X}, \|\delta\|_2 \leq 1} f(x+\delta) - f(x).$$

- gradient penalty

$$U = \left\{ \frac{\Phi(x) - \Phi(y)}{\|x - y\|_2} : x, y \in \mathcal{X} \right\} \Rightarrow \|\nabla f\| = \sup_{x \in \mathcal{X}} \|\nabla f(x)\|_2.$$

- deformation stability penalty

$$U = \{\Phi(L_\tau x) - \Phi(x) : x \ \in \ \mathcal{X}, \ \tau\}$$
$$\Rightarrow \|f\|_\tau^2 = \sup_{\substack{x \in \mathcal{X} \\ \tau \text{ small deformation}}} f(L_\tau x) - f(x).$$

- use CKN kernel approximations (work in progress).

see [Bietti et al., 2019] and references therein