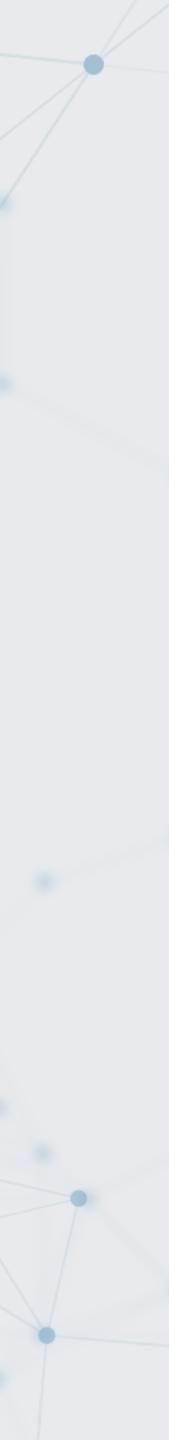


.



# **Dynamic Deep Learning** A paradigm shift in AI research and Tools

**Soumith Chintala** Facebook AI Research

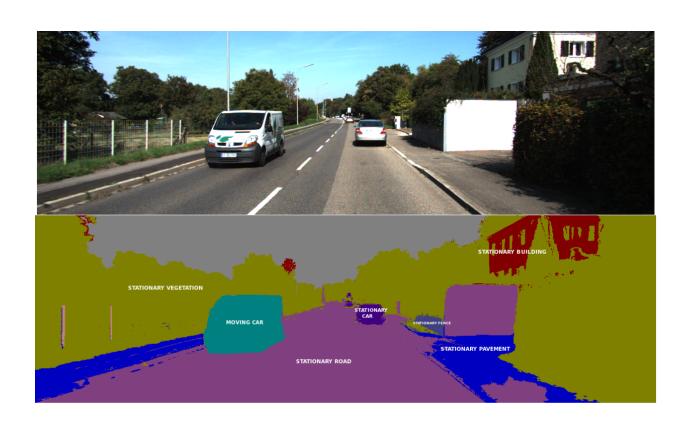




# Examples in products and research

### A Dynamic Trend







# Tools for Al keeping up with change



K

### theano

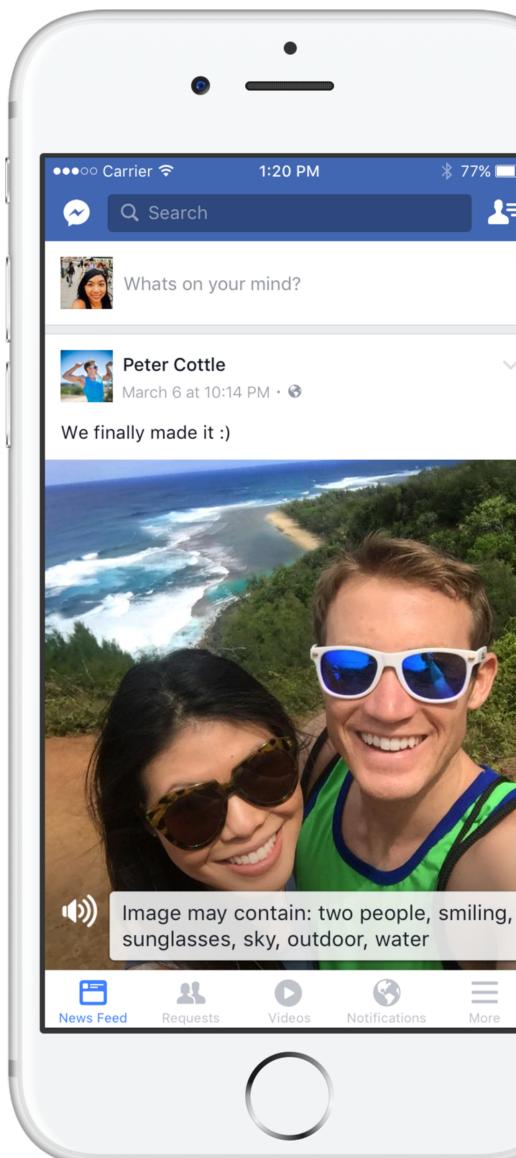
Caffe

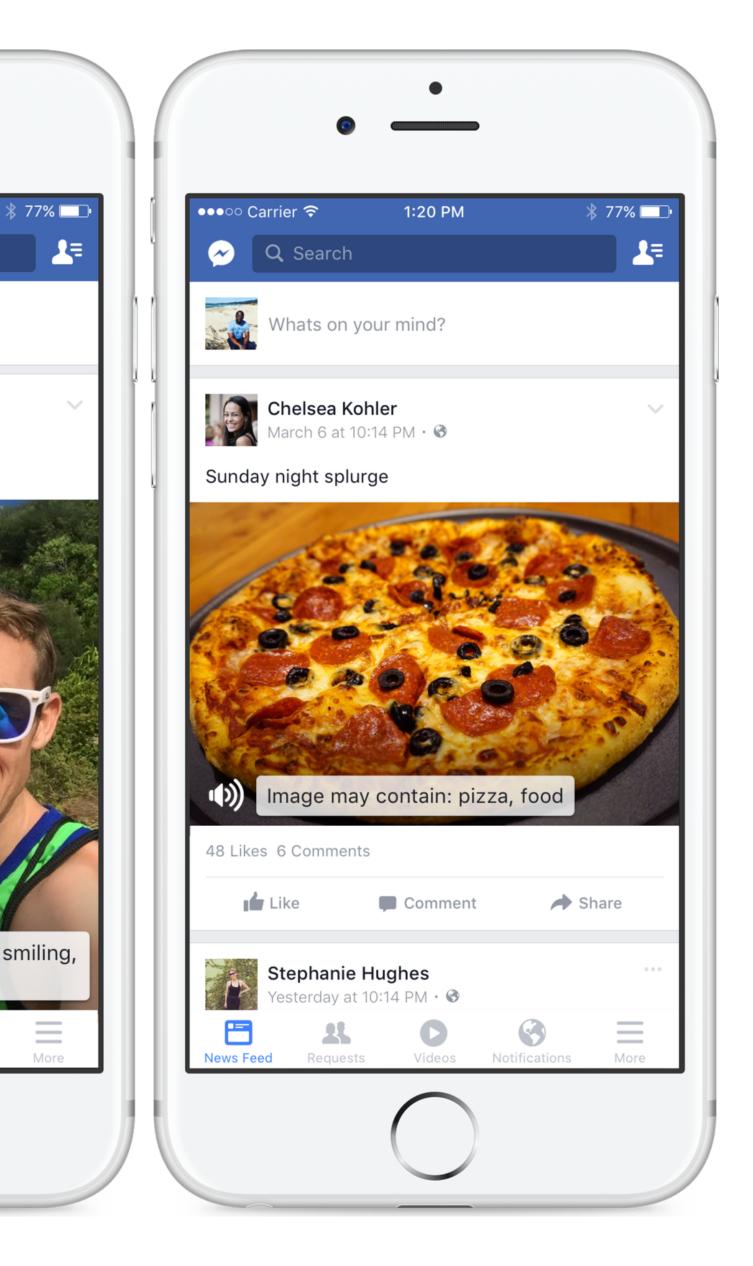


# Examples of AI Today



# Captioning









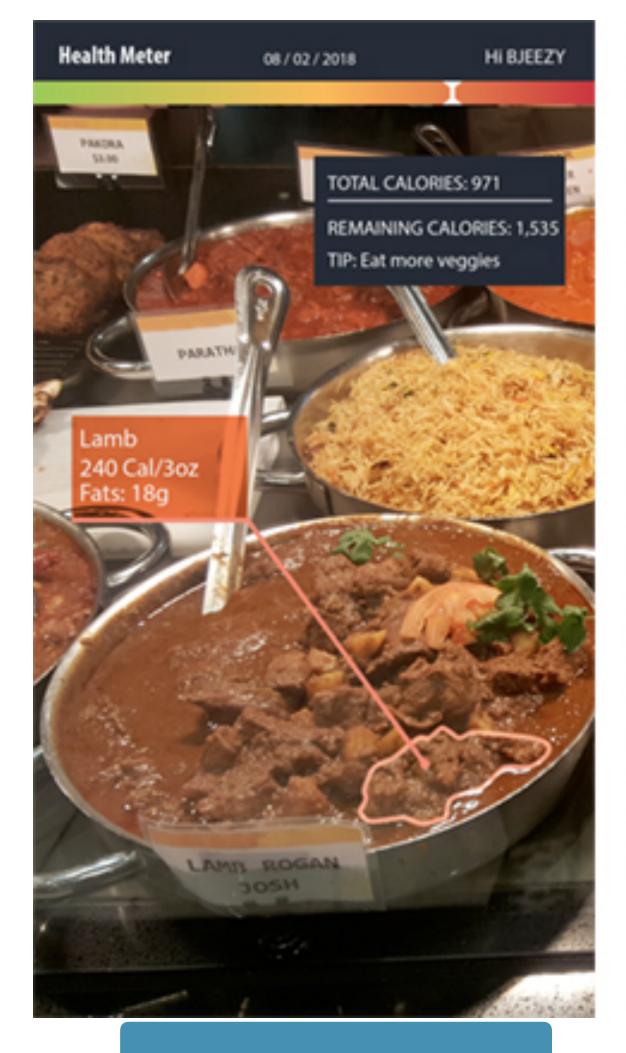
# Self Driving Cars



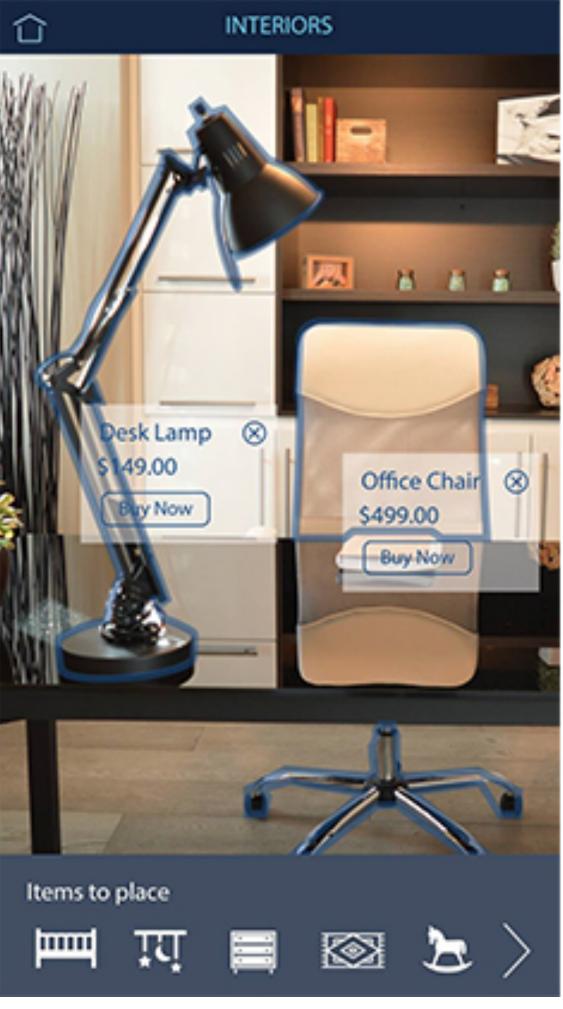


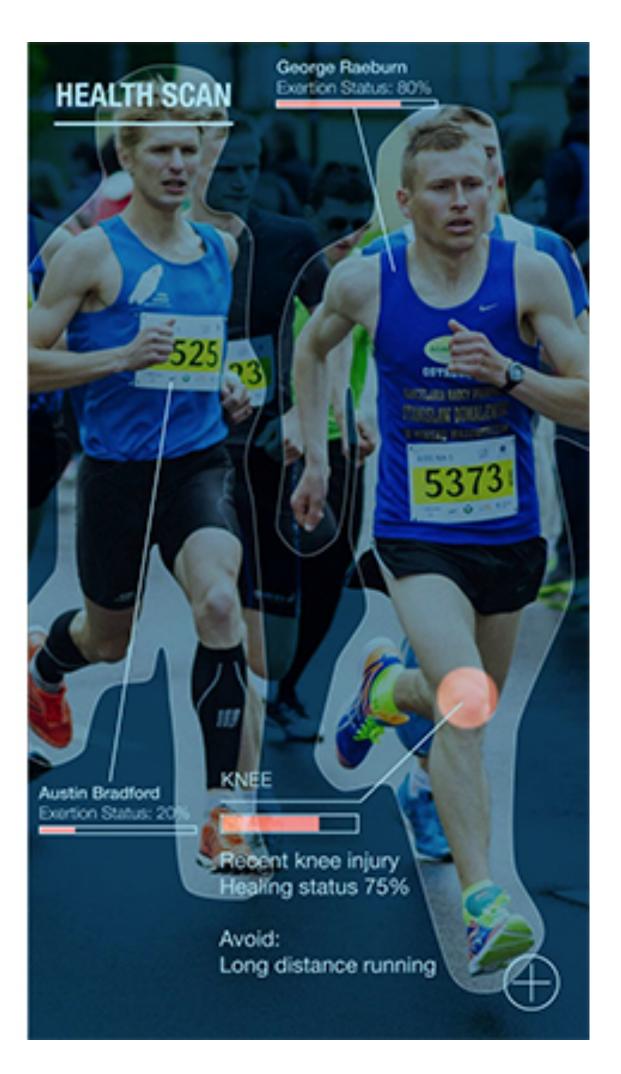


# Smart Apps













# **Machine Translation**

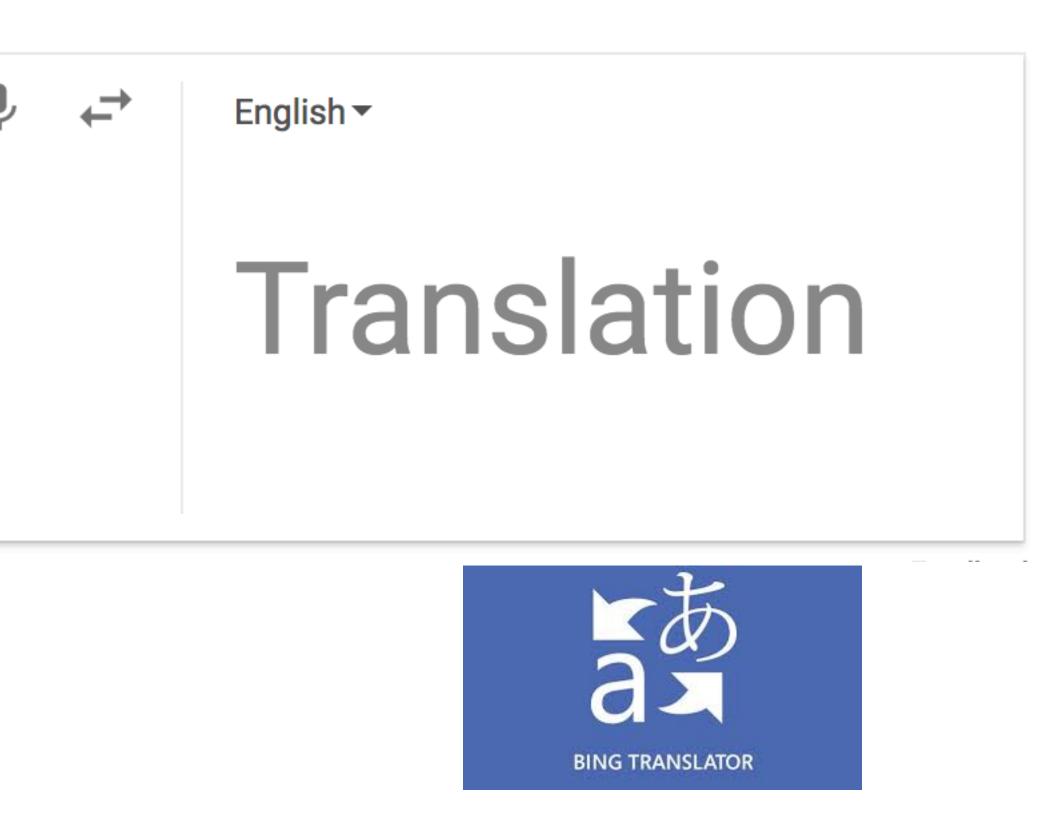
Detect language▼

# Enter text



Examples





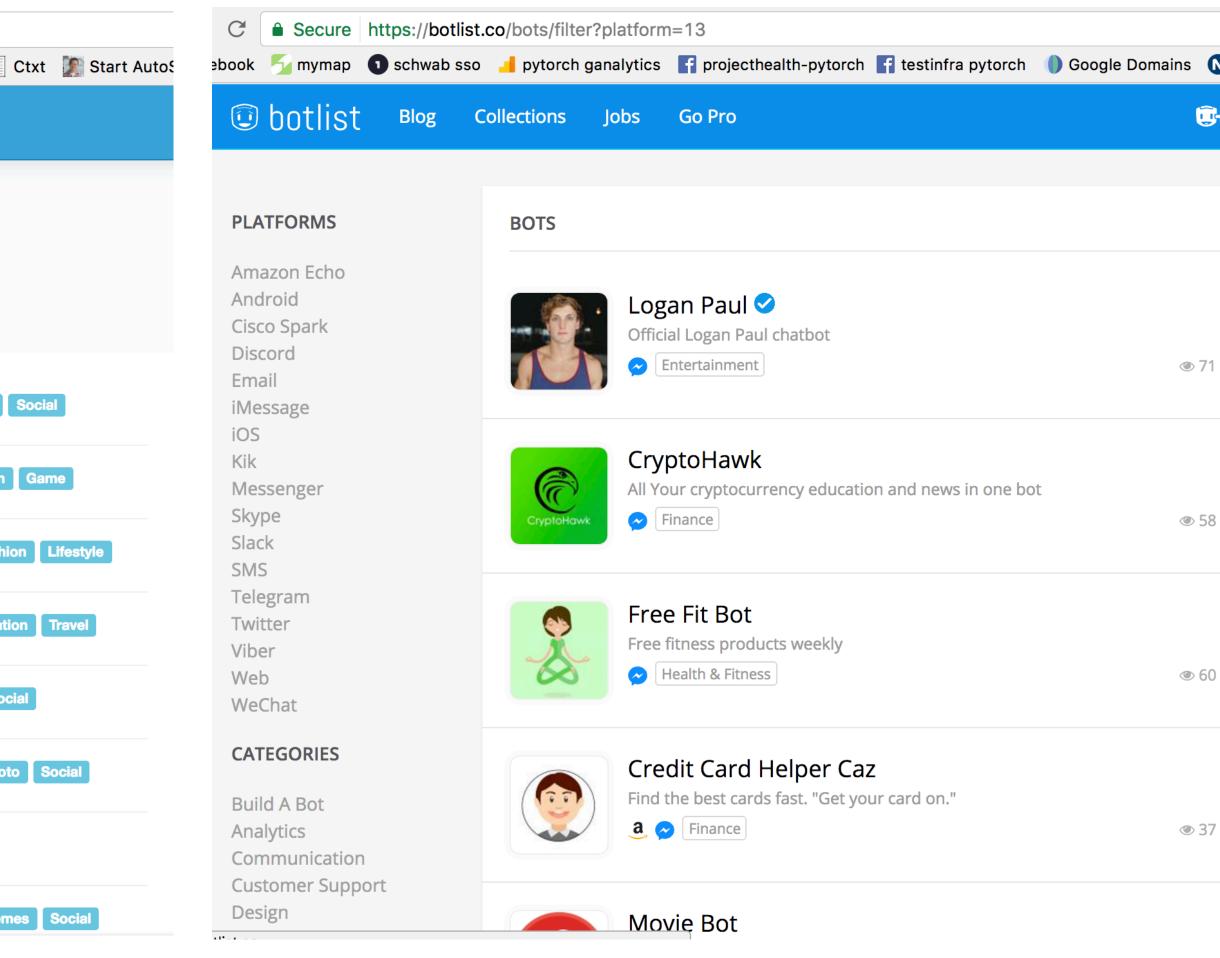




# Chatbots

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tBottle												
		Mes	senger	Skype	Telegram	Slack	Kik	Туре у	our query	here	٩	
		Found 1180 Chatbots for Facebook Messenger										
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### Examples







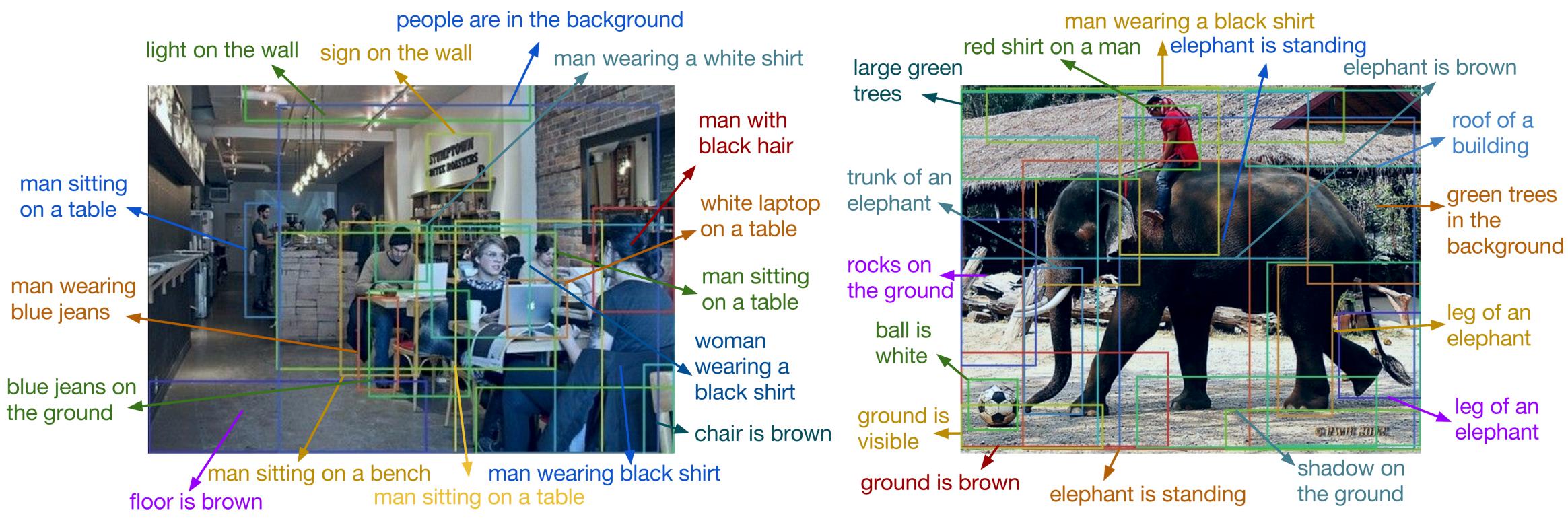
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7	<b>9</b> 0	♡0					

# Image Understanding





# Image Understanding Dense ap by Justin Johnson & group https://github.com/jcjohnson/densecap

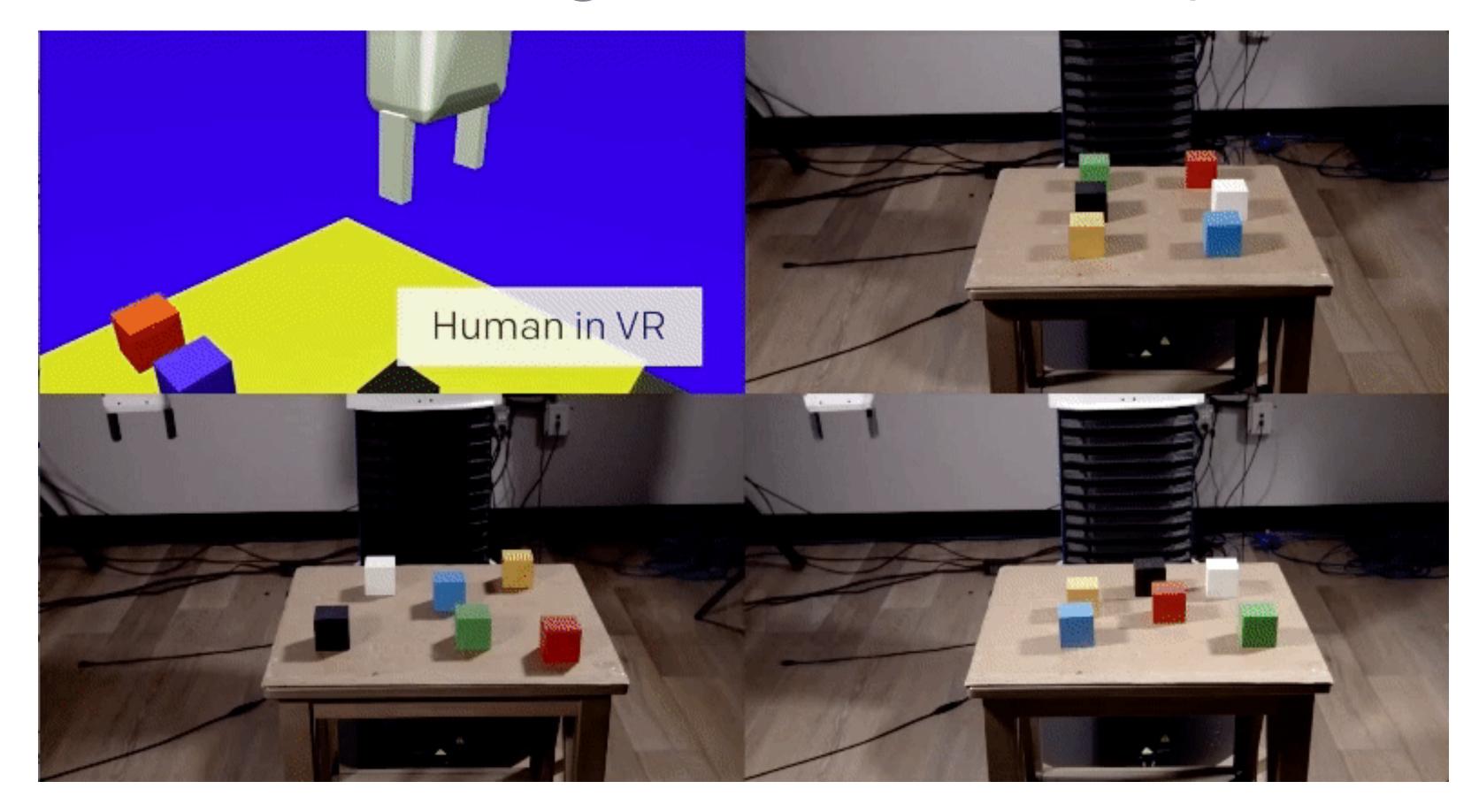


### Examples

Trends



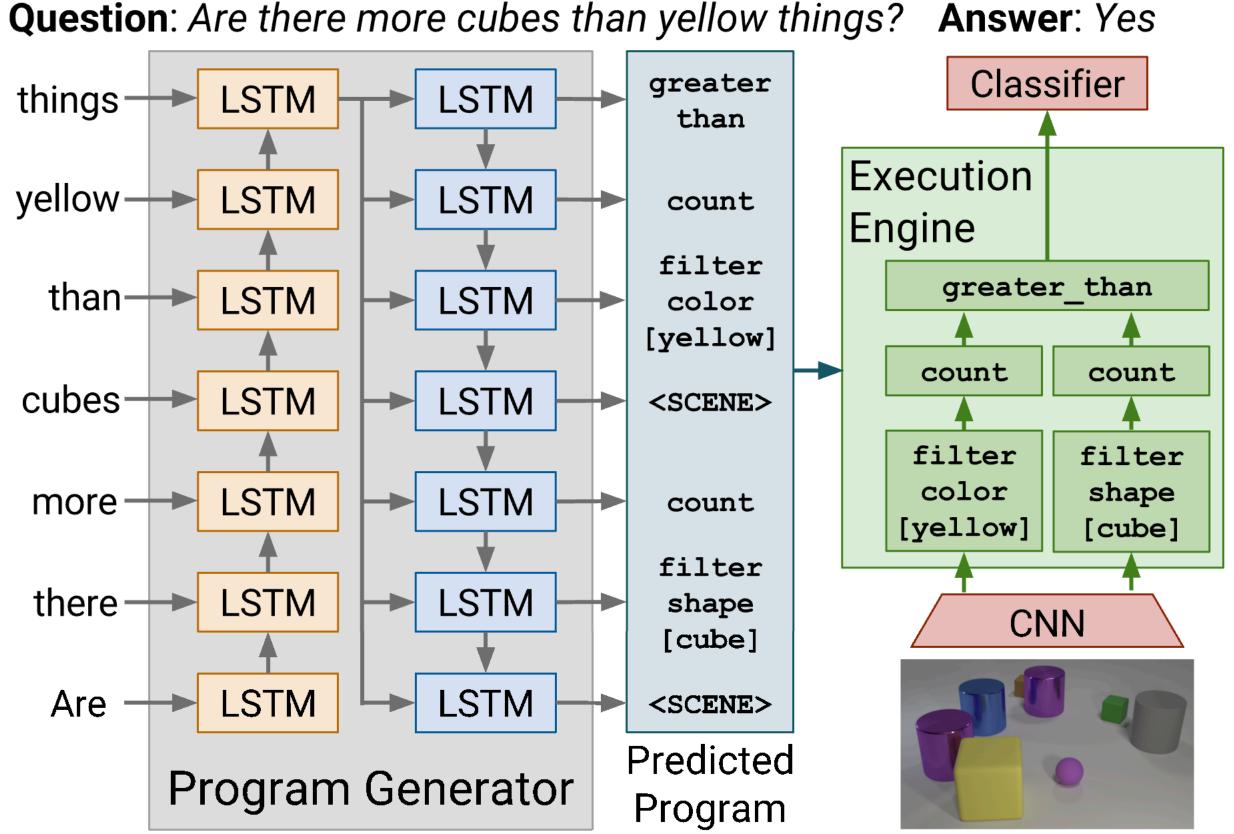
## **Robotics** One-shot imitation learning - Duan et. al. at OpenAl







# **Question Answering**



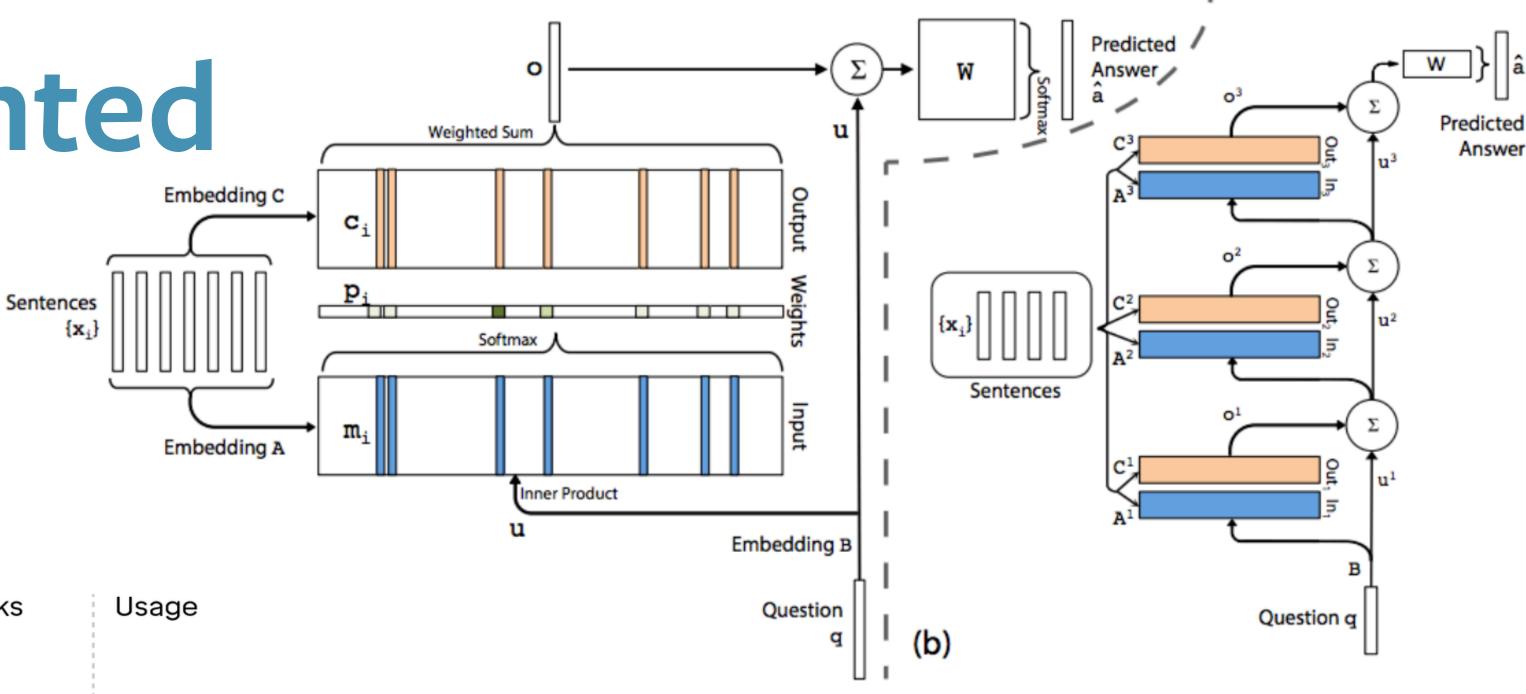
### Examples

### Inferring and Executing Programs for Visual Reasoning - Johnson et. al. at Facebook

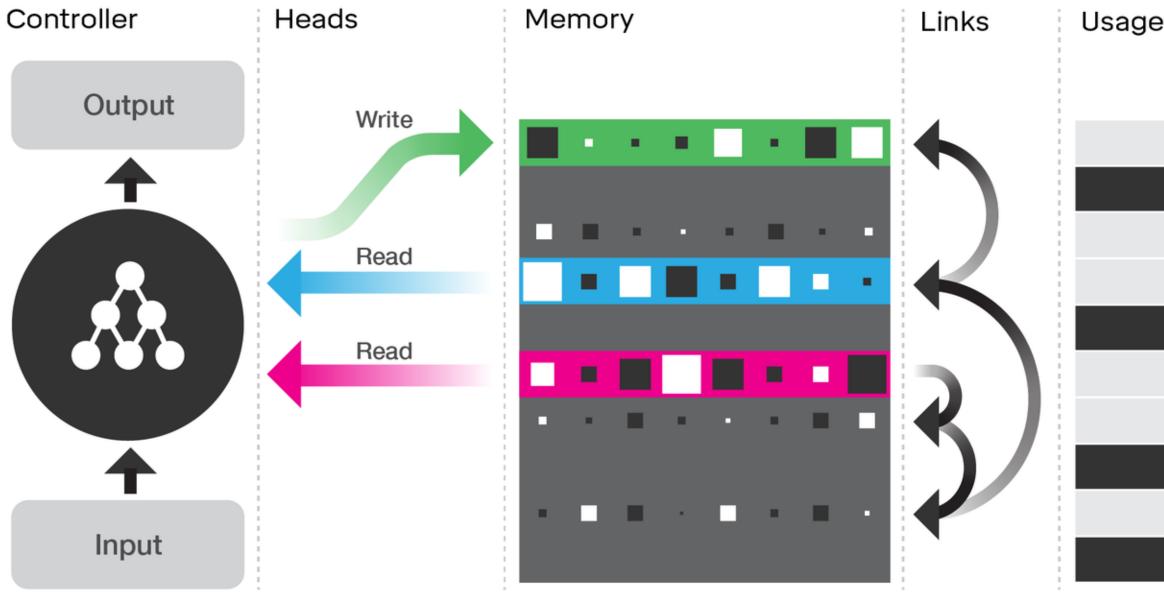




# Memory Augmented



### Illustration of the DNC architecture

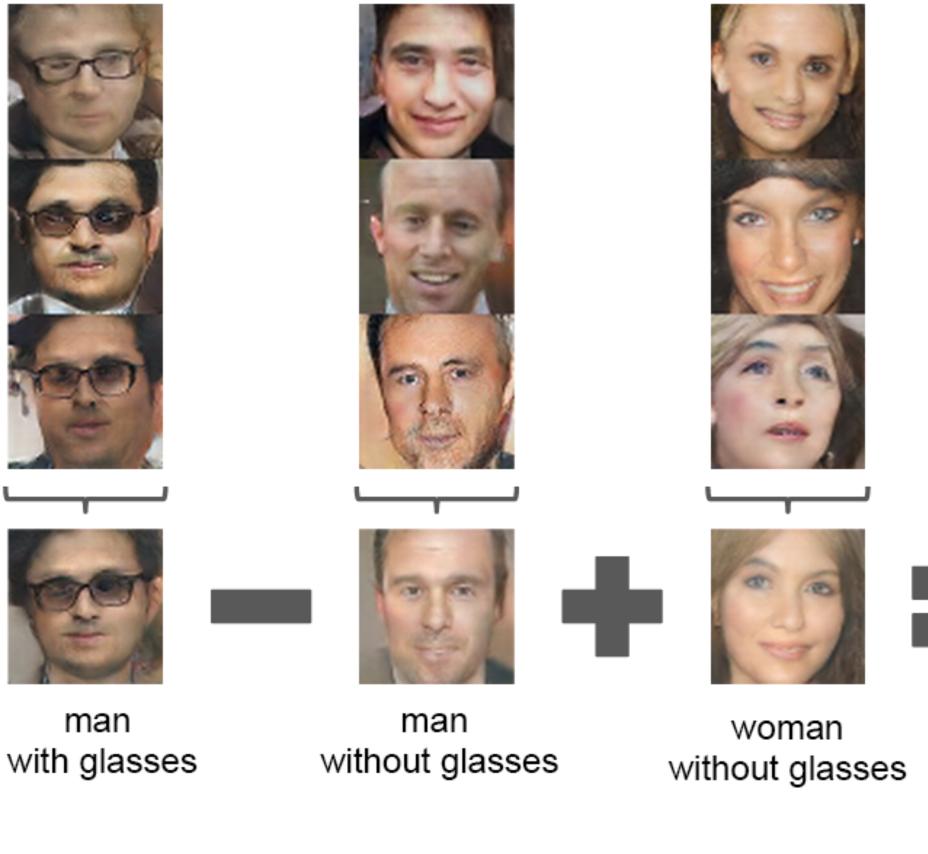


### Examples

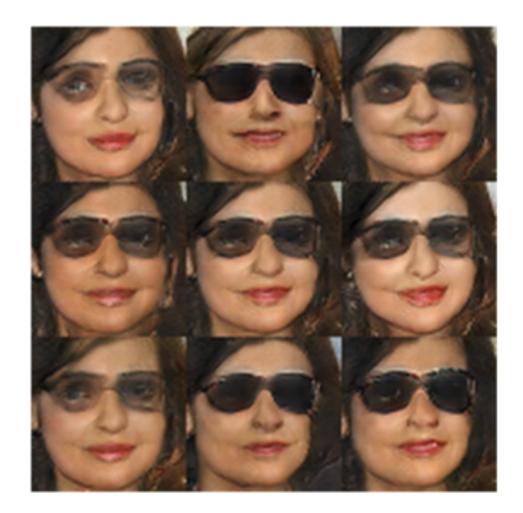
### Memory Networks - Facebook Differentiable Neural Computer - Deepmind

Trends Tools for AI

# **Adversarial Networks** DCGAN by Radford et. al.



Examples



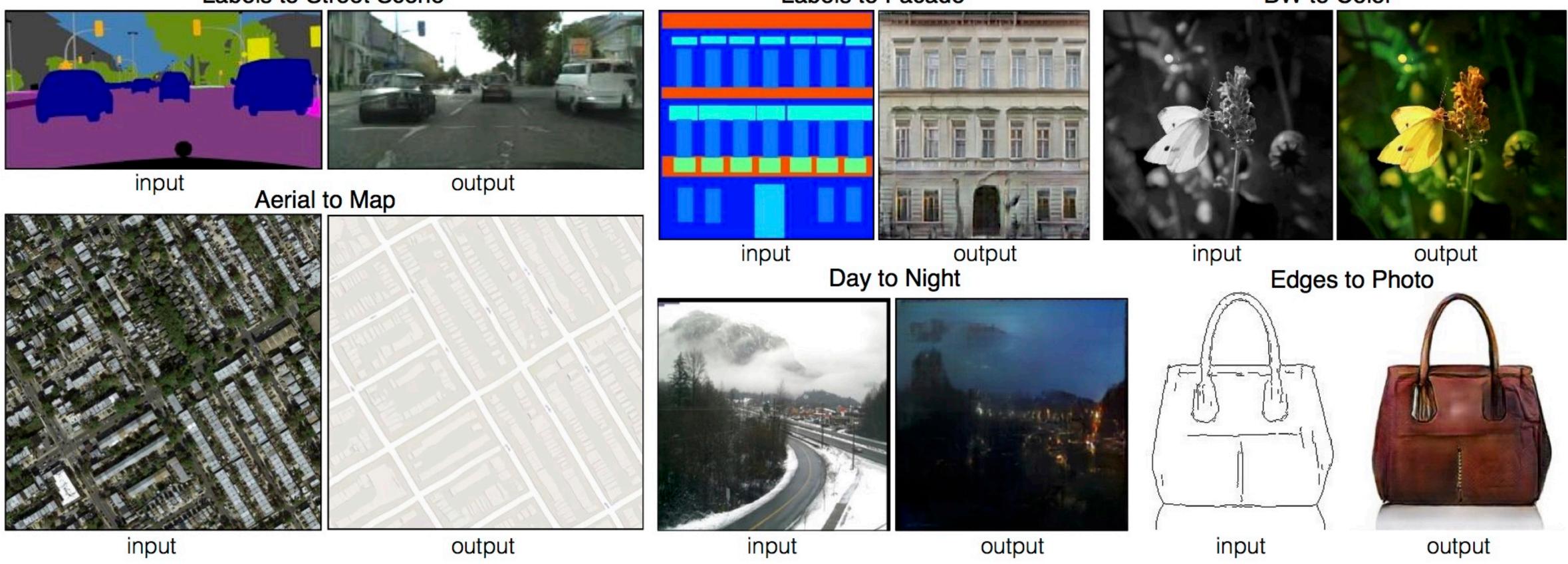
woman with glasses





### **Adversarial Nets** pix2pix by Isola, Zhu, Zhou, Efros @ UCBerkeley

Labels to Street Scene



Examples

Labels to Facade

BW to Color



# Adversarial Nets



### Examples

### Cycle GAN by Zhu, Park, Isola, Efros @ UCBerkeley









### Cars



### Examples

### Video games





Measurement and training for artificial intelligence.

Internet

Trends

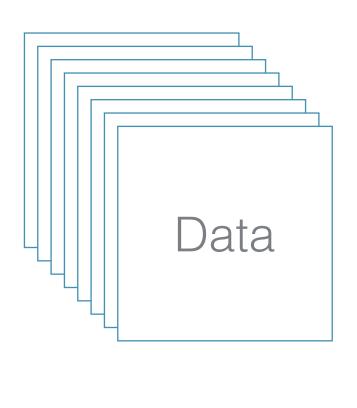








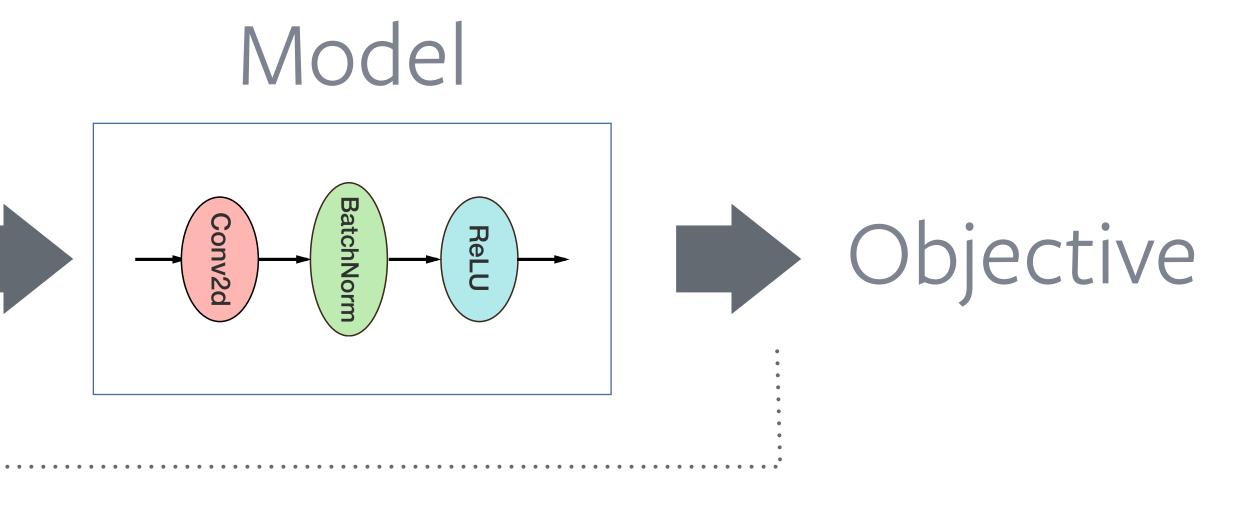
### **Train Model**



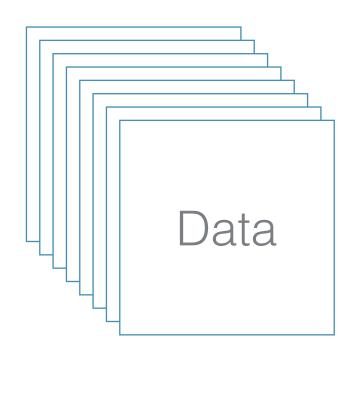
••••

Trends





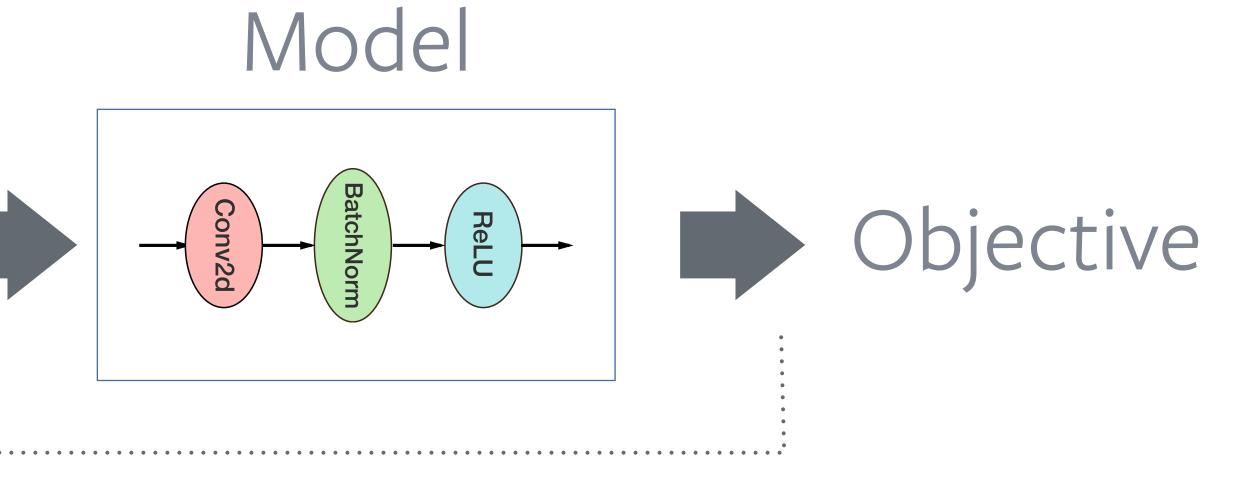
### **Train Model**

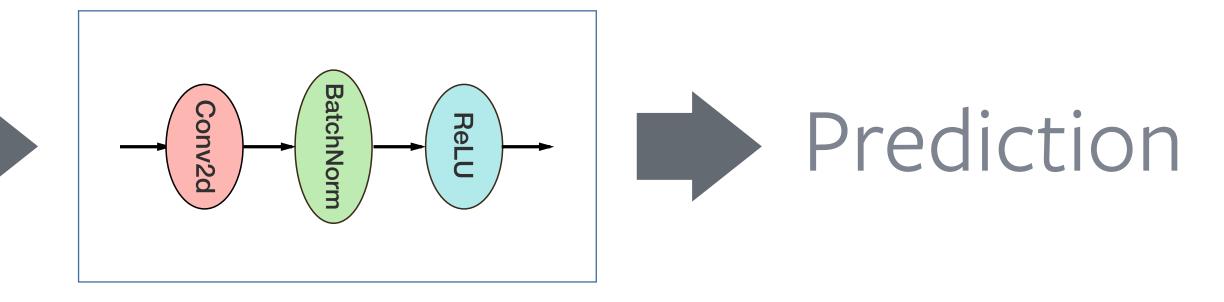


### Deploy & Use



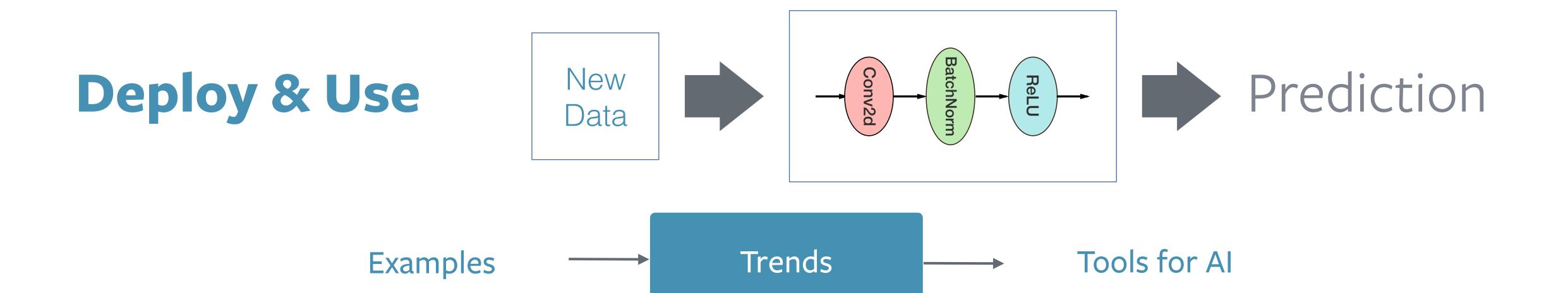


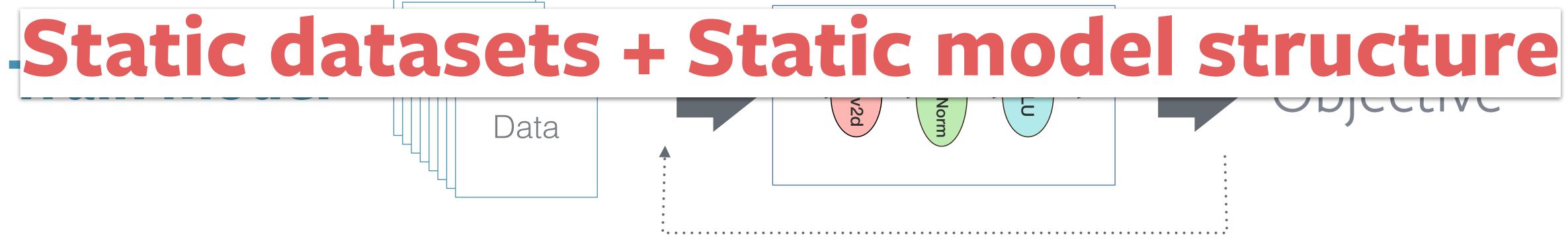


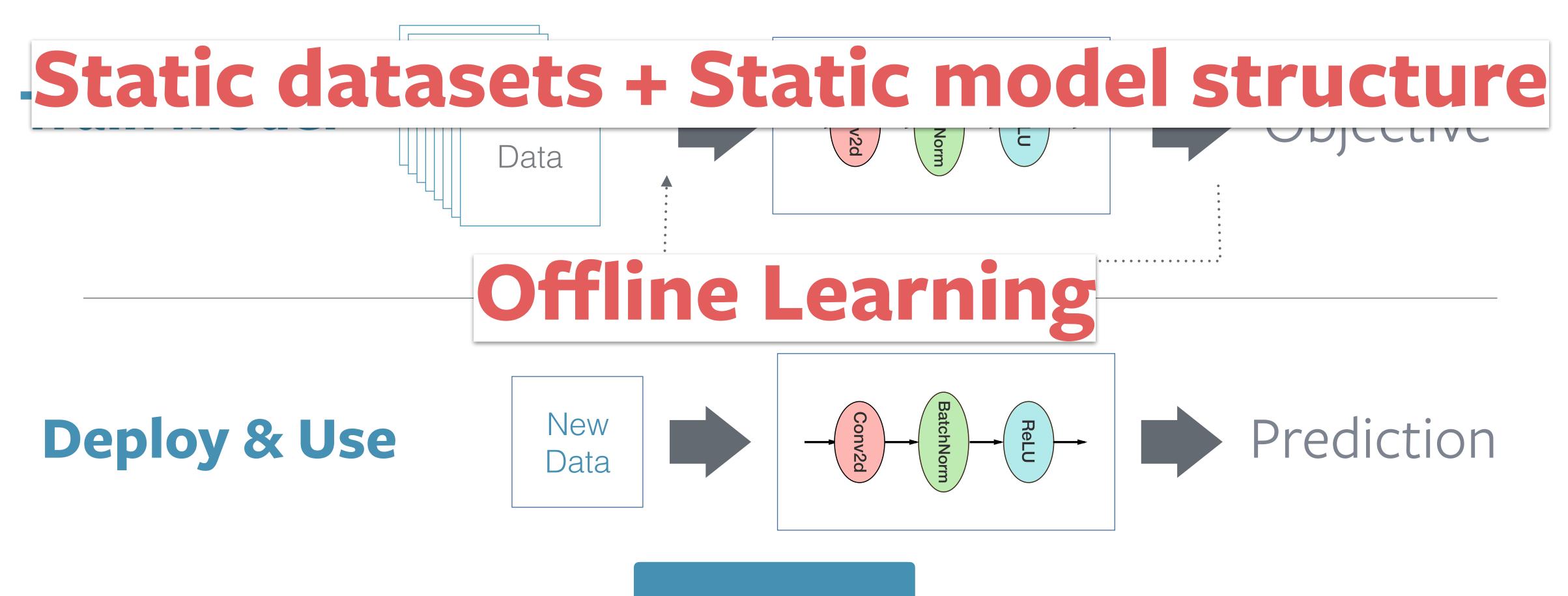


Trends

# Data







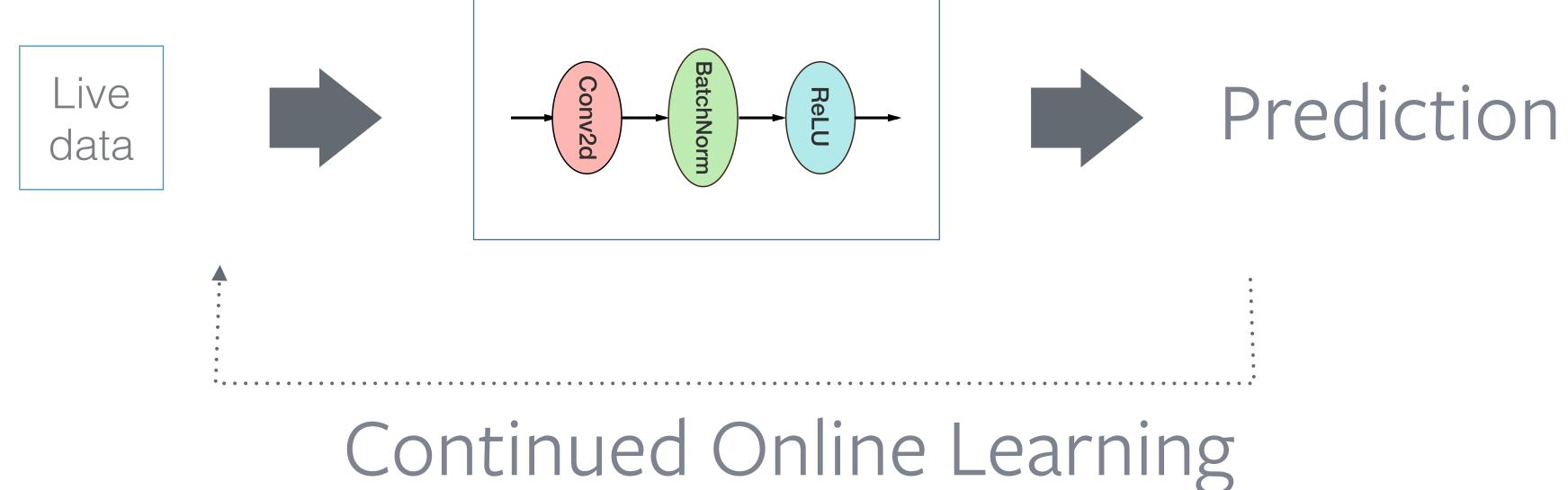
Examples

### Trends





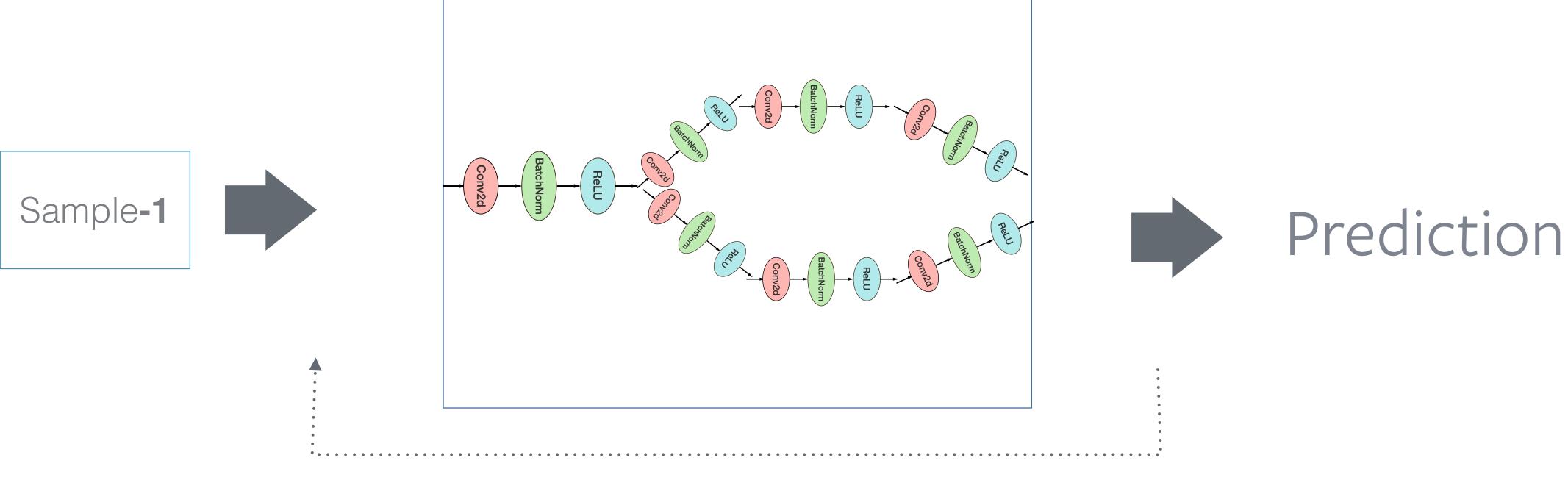








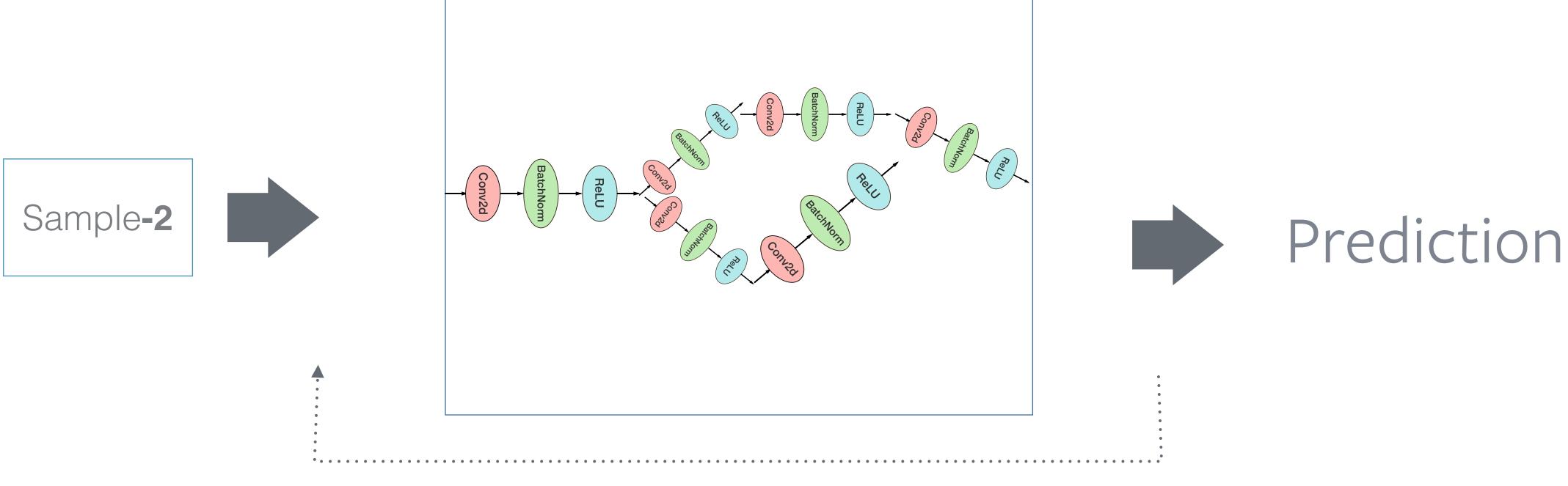




### Data-dependent change in model structure



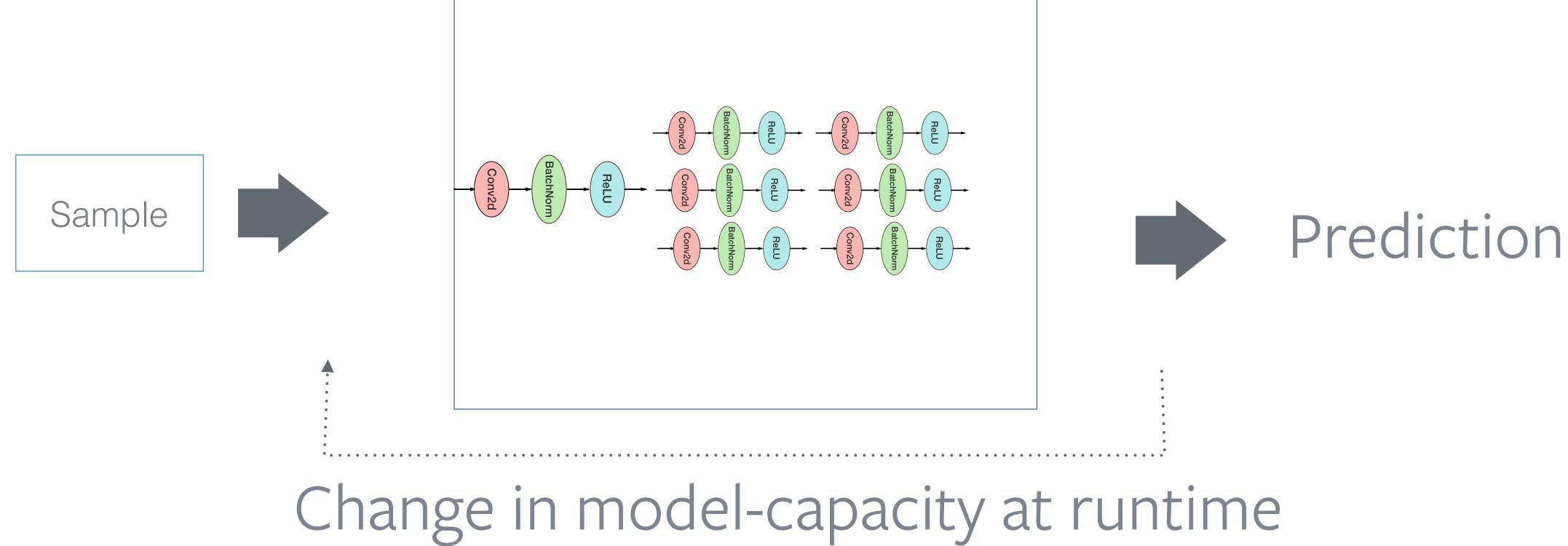




### Data-dependent change in model structure

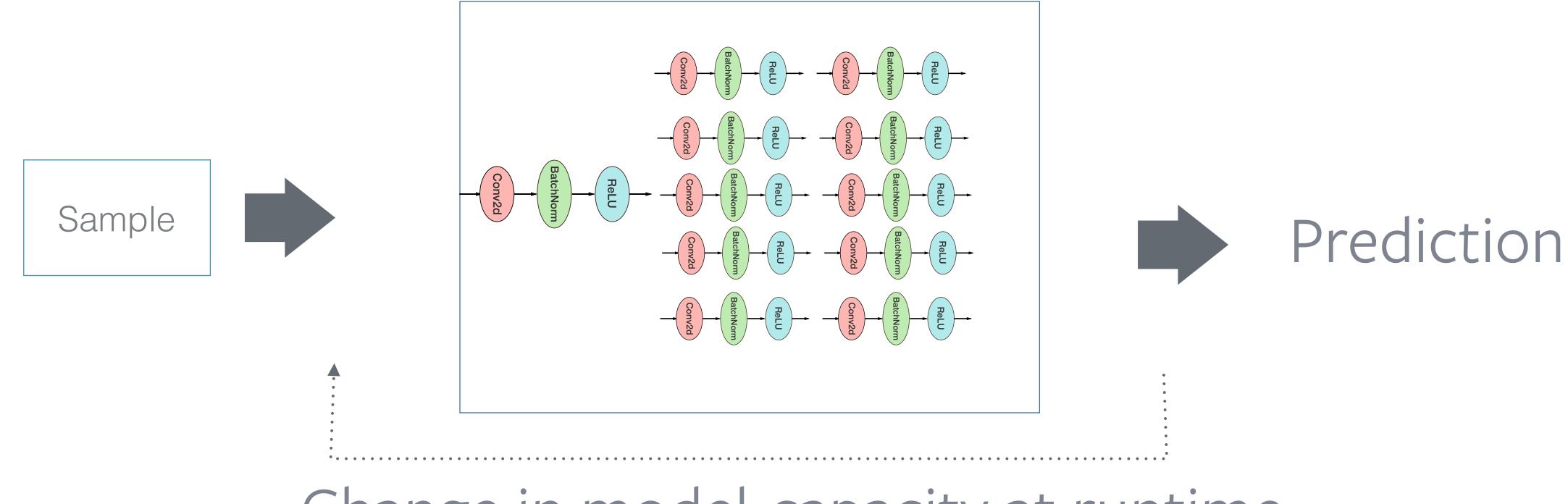












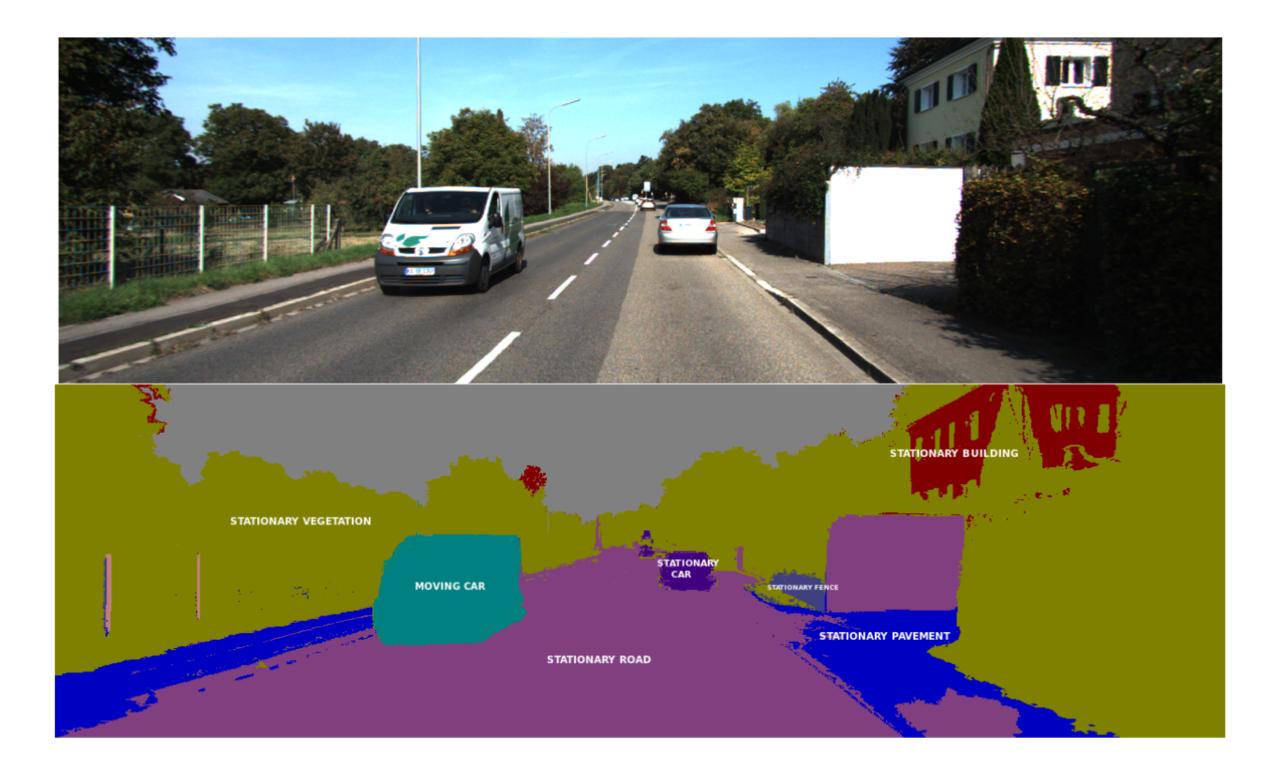
### Change in model-capacity at runtime



Tools for AI

Trends

# **The dynamic kind** Self-driving Cars

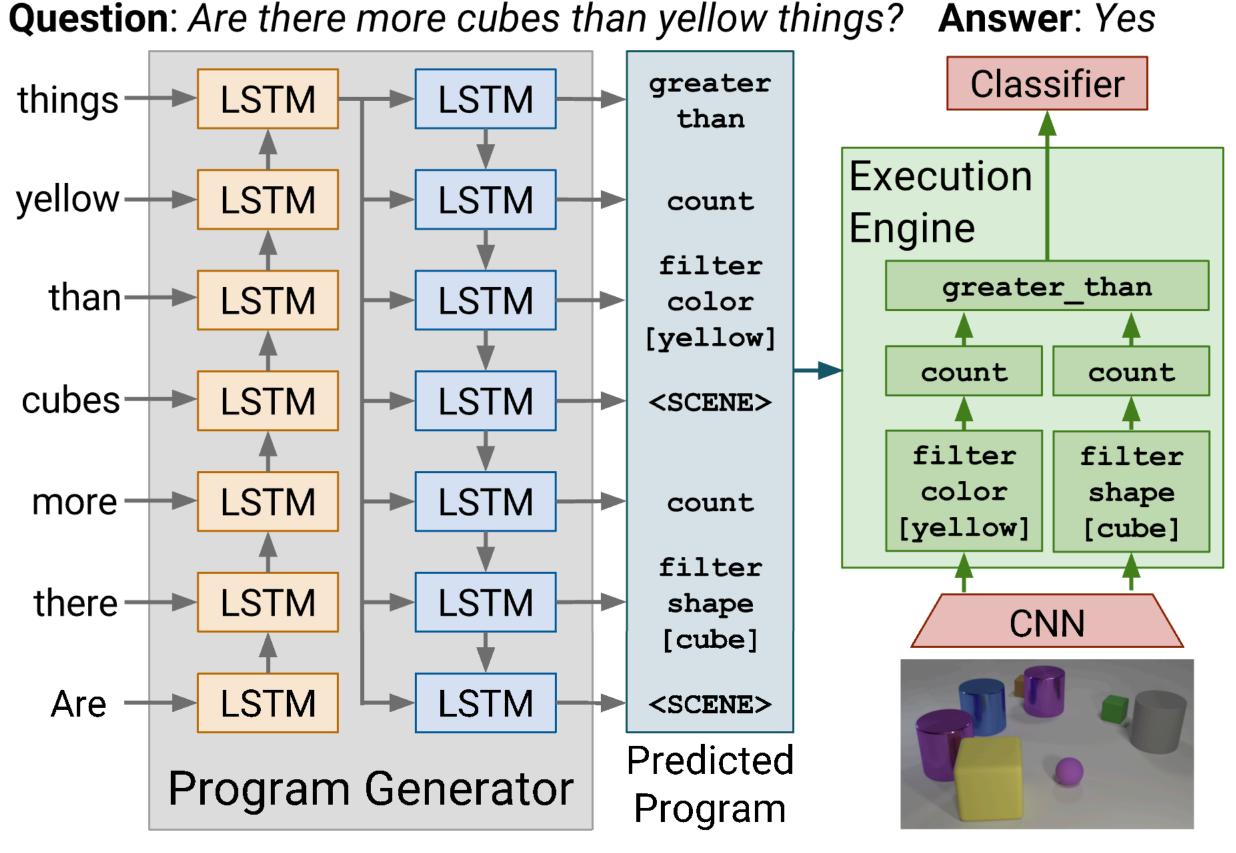








# The dynamic kind Inferring and Executing Programs for Visual Reasoning



Examples

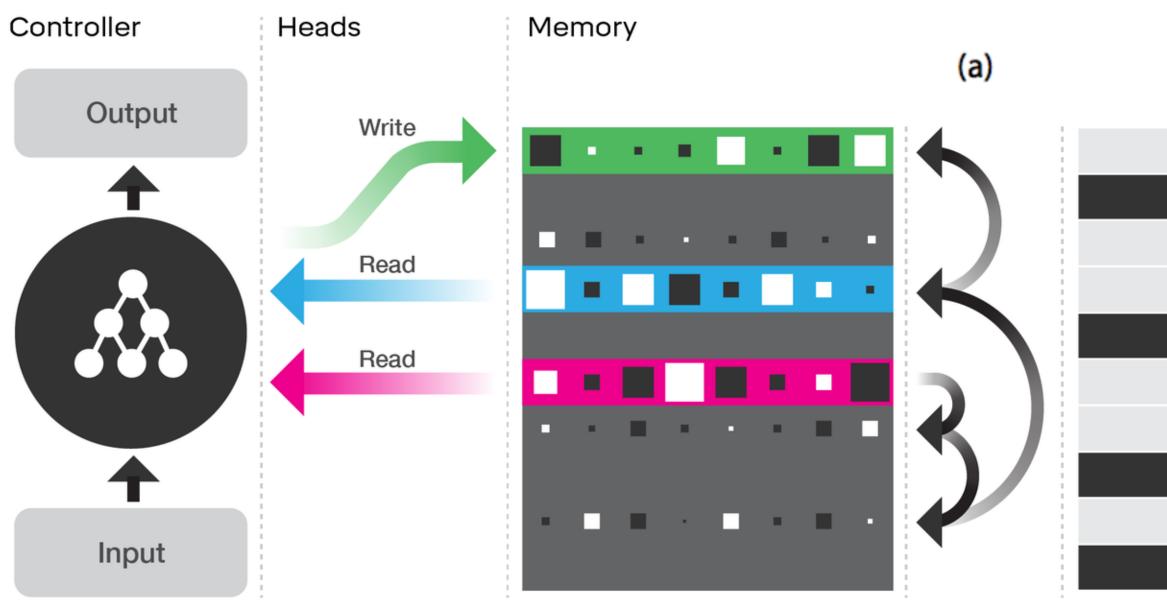
# - Johnson et. al. at Facebook

Trends



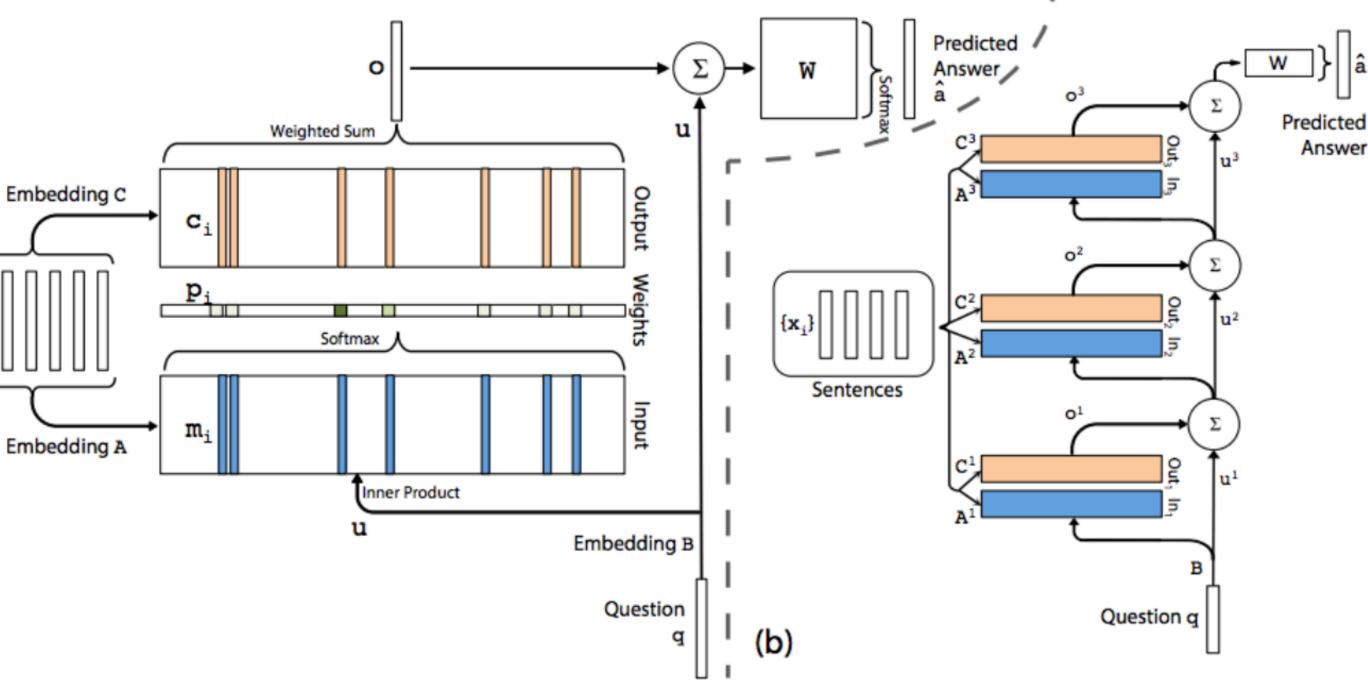
### The dynamic kind Memory augmented Sentences $\{\mathbf{x}_i\}$

Illustration of the DNC architecture



### Examples

Trends



### Memory Networks - Facebook Differentiable Neural Computer - Deepmind





Cars





### Video games





Measurement and training for artificial intelligence.

Internet

### Trends

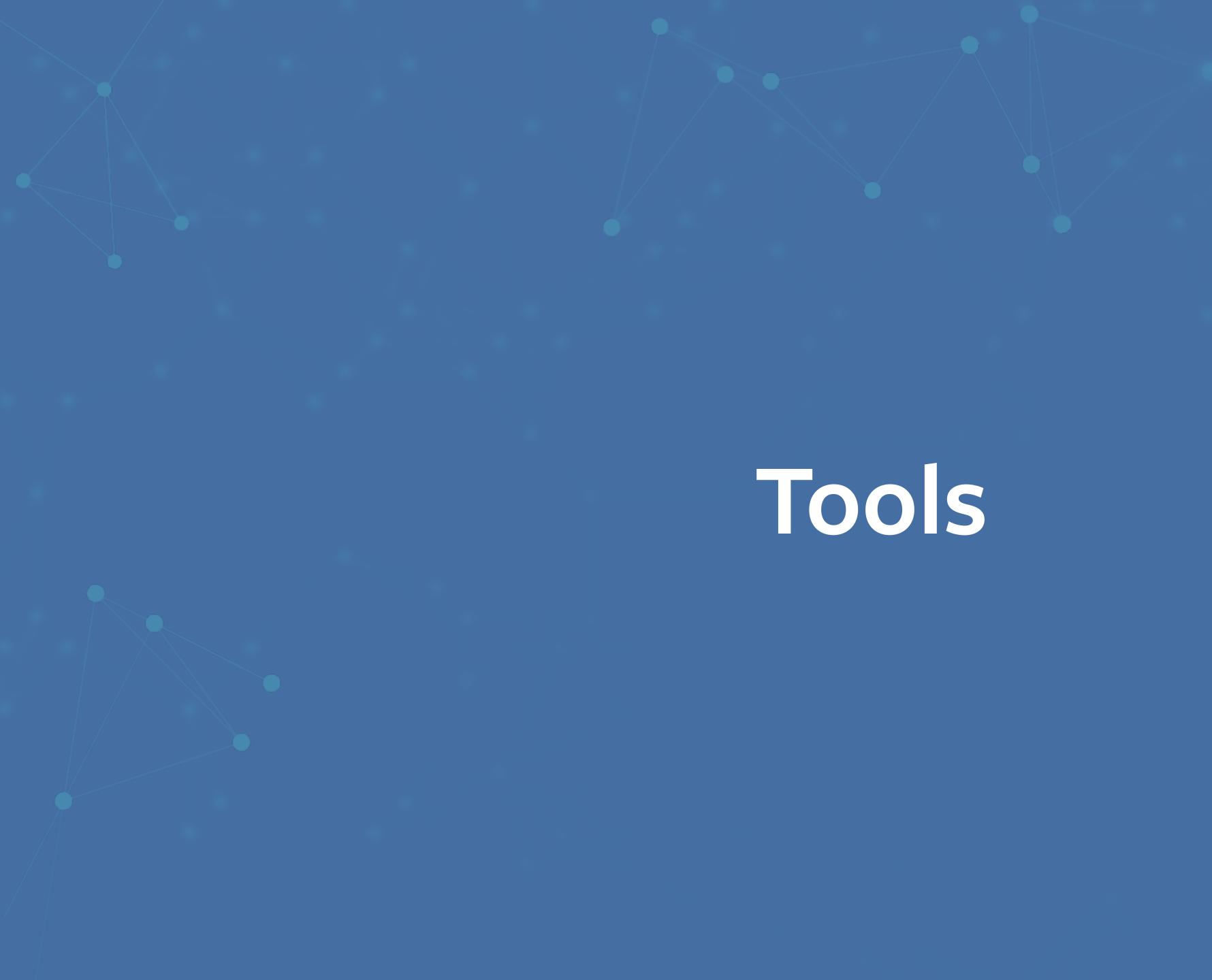


### self-adding new memory or layers changing evaluation path based on inputs online learning













# A next-gen framework for Al

- Interop with many dynamic environments
  - Connecting to car sensors should be as easy as training on a dataset
  - Connect to environments such as OpenAl Universe





- Interop with many dynamic environments
  - Connecting to car sensors should be as easy as training on a dataset
    Connect to environments such as OpenAl Universe
- •Dynamic Neural Networks
  - Change behavior and structure of neural network at runtime



Trends



- Interop with many dynamic environments
  - Connecting to car sensors should be as easy as training on a dataset - Connect to environments such as OpenAl Universe
- Dynamic Neural Networks
- Change behavior and structure of neural network at runtime
- Minimal Abstractions
- more complex AI systems means harder to debug without a simple API







- Interop with many dynamic environments
  - Connecting to car sensors should be as easy as training on a dataset
    Connect to environments such as OpenAI Universe
- Dynamic Noural Notworks
- Dynamic Neural Networks
- Change behavior and structure of neural network at runtime
- Minimal Abstractions
  - more complex AI systems means harder to debug without a simple API

•FAST



### Trends

- Interop with many dynamic environments
  - Connecting to car sensors should be as easy as training on a dataset
    Connect to environments such as OpenAI Universe
- •Dynamic Neural Networks
  - Change behavior and structure of neural network at runtime
- Minimal Abstractions
- more complex AI systems means harder to debug without a simple API
   FAST





# **Tools for AI research and deployment** Many machine learning tools and deep learning frameworks PYTÖRCH





### theano Caffe

Examples

mxnet







Trends

### **Tools for AI research and deployment** Static graph frameworks







### Caffe

theano





Dynamic graph frameworks (more naturally enable dynamic deep learning) PYTÖRCH xnet



Trends

### Static graph Frameworks

- Model is constructed and compiled once and reused many times
- Hard to change the model on the fly
- harder to debug in a complex system







### Dynamic graph Frameworks

- Model is constructed on the fly at runtime
- •Change behavior, structure of model
- Imperative style of programming

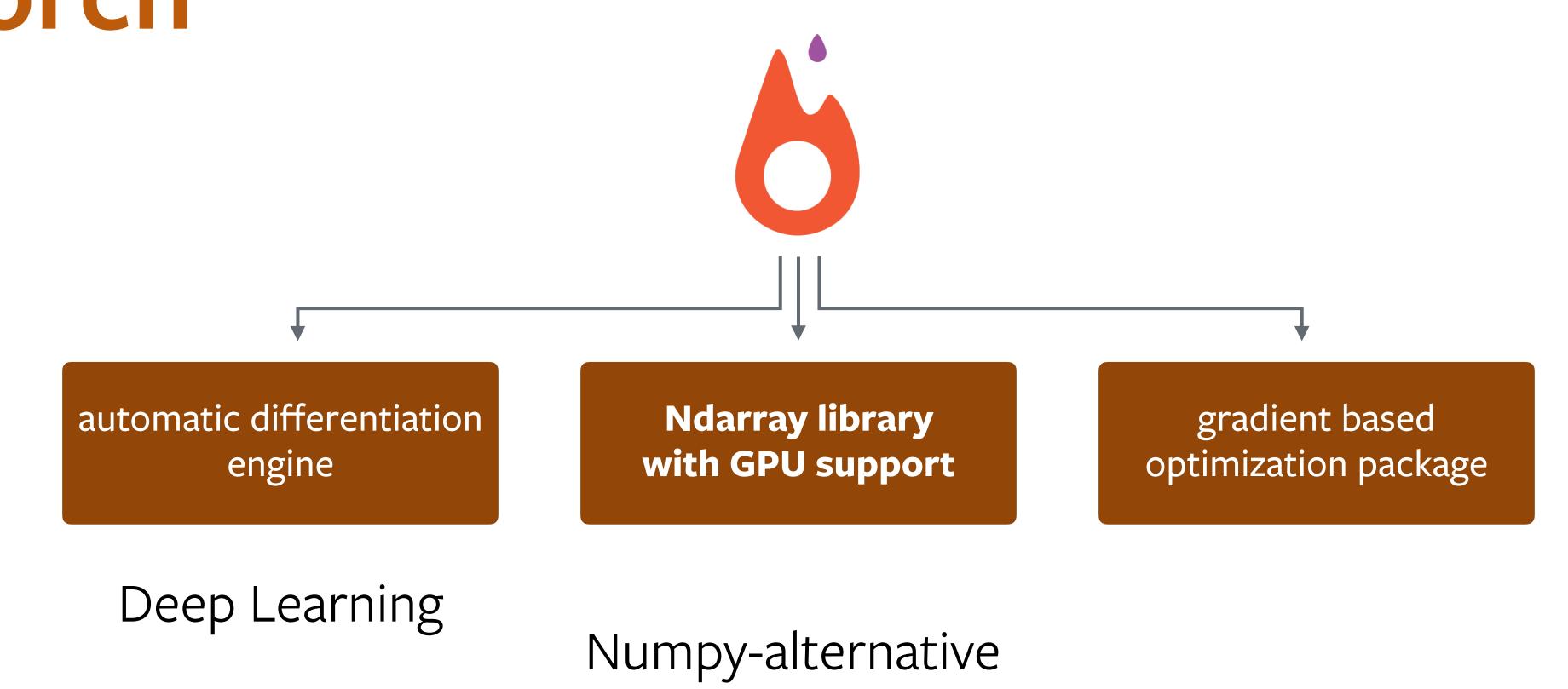


### el PYTÖRCH



Trends





Reinforcement Learning

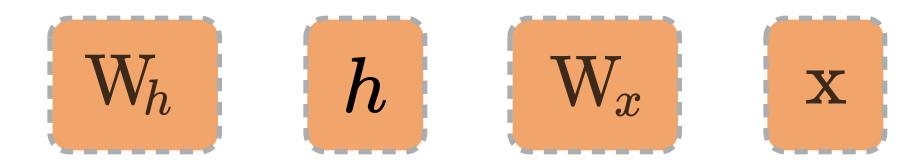


```
# -*- coding: utf-8 -*-
                                                                            import torch
import numpy as np
                                                                            dtype = torch.FloatTensor
# N is batch size; D_in is input dimension;
                                                                            # dtype = torch.cuda.FloatTensor # Uncomment this to run on GPU
# H is hidden dimension; D_out is output dimension.
N, D_in, H, D_out = 64, 1000, 100, 10
                                                                            # N is batch size; D_in is input dimension;
                                                                            # H is hidden dimension; D_out is output dimension.
# Create random input and output data
                                                                            N, D_in, H, D_out = 64, 1000, 100, 10
x = np.random.randn(N, D_in)
y = np.random.randn(N, D_out)
                                                                            # Create random input and output data
                                                                            x = torch.randn(N, D_in).type(dtype)
# Randomly initialize weights
                                                                            y = torch.randn(N, D_out).type(dtype)
                                                                                                                         PyTorch
w1 = np.random.randn(D_in, H)
                                               Numpy
                                                                            # Randomly initialize weights
w^2 = np.random.randn(H, D out)
                                                                            w1 = torch.randn(D_in, H).type(dtype)
                                                                            w2 = torch.randn(H, D_out).type(dtype)
learning_rate = 1e-6
for t in range(500):
                                                                            learning_rate = 1e-6
    # Forward pass: compute predicted y
                                                                            for t in range(500):
    h = x.dot(w1)
                                                                                # Forward pass: compute predicted y
    h_relu = np.maximum(h, 0)
                                                                                h = x.mm(w1)
    y_pred = h_relu.dot(w2)
                                                                                h_relu = h.clamp(min=0)
                                                                                y_pred = h_relu.mm(w2)
    # Compute and print loss
                                                                                # Compute and print loss
    loss = np.square(y_pred - y).sum()
                                                                                loss = (y_pred - y).pow(2).sum()
    print(t, loss)
                                                                                print(t, loss)
    # Backprop to compute gradients of w1 and w2 with respect to loss
                                                                                # Backprop to compute gradients of w1 and w2 with respect to loss
    grad_y_pred = 2.0 * (y_pred - y)
                                                                                grad_y_pred = 2.0 * (y_pred - y)
    grad_w2 = h_relu.T.dot(grad_y_pred)
                                                                                grad_w2 = h_relu.t().mm(grad_y_pred)
    grad_h_relu = grad_y_pred.dot(w2.T)
                                                                                grad_h_relu = grad_y_pred.mm(w2.t())
    grad_h = grad_h_relu.copy()
                                                                                grad_h = grad_h_relu.clone()
    grad_h[h < 0] = 0
                                                                                grad_h[h < 0] = 0
    grad_w1 = x.T.dot(grad_h)
                                                                                grad_w1 = x.t().mm(grad_h)
    # Update weights
                                                                                # Update weights using gradient descent
    w1 -= learning_rate * grad_w1
                                                                                w1 -= learning_rate * grad_w1
                                                                                w2 -= learning_rate * grad_w2
    w2 -= learning_rate * grad_w2
```

from torch.autograd import Variable

from torch.autograd import Variable

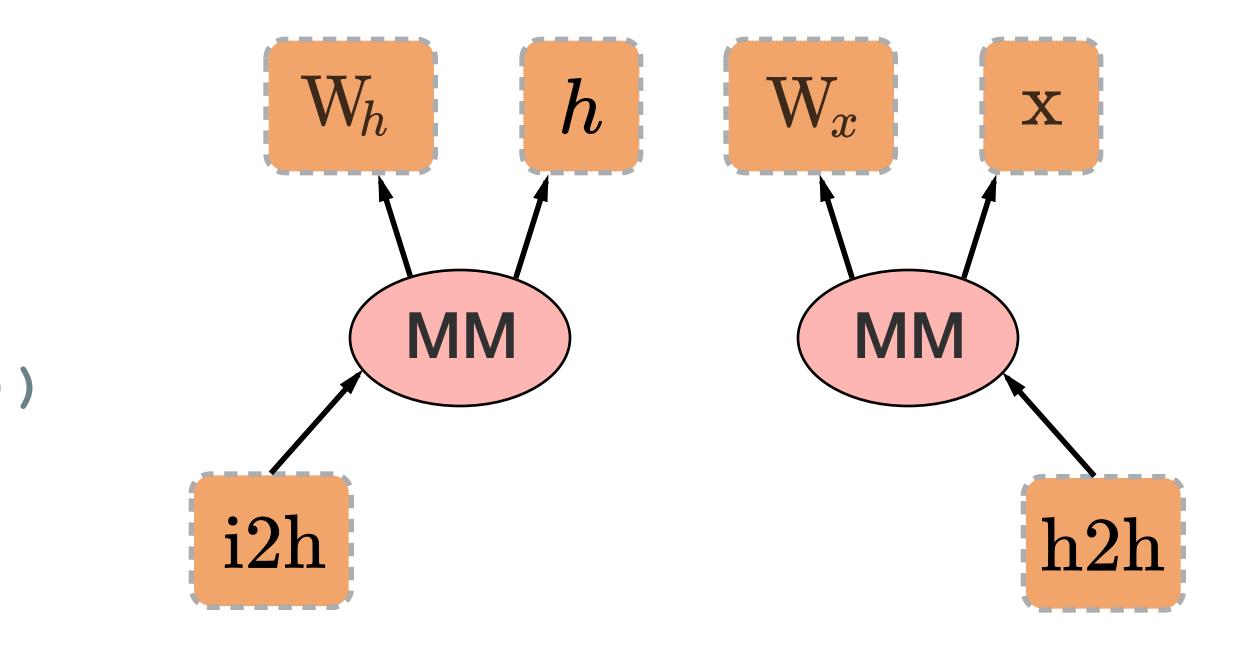
x = Variable(torch.randn(1, 10))prev h = Variable(torch.randn(1, 20)) W h = Variable(torch.randn(20, 20))W x = Variable(torch.randn(20, 10))



from torch.autograd import Variable

x = Variable(torch.randn(1, 10))
prev\_h = Variable(torch.randn(1, 20))
W\_h = Variable(torch.randn(20, 20))
W\_x = Variable(torch.randn(20, 10))

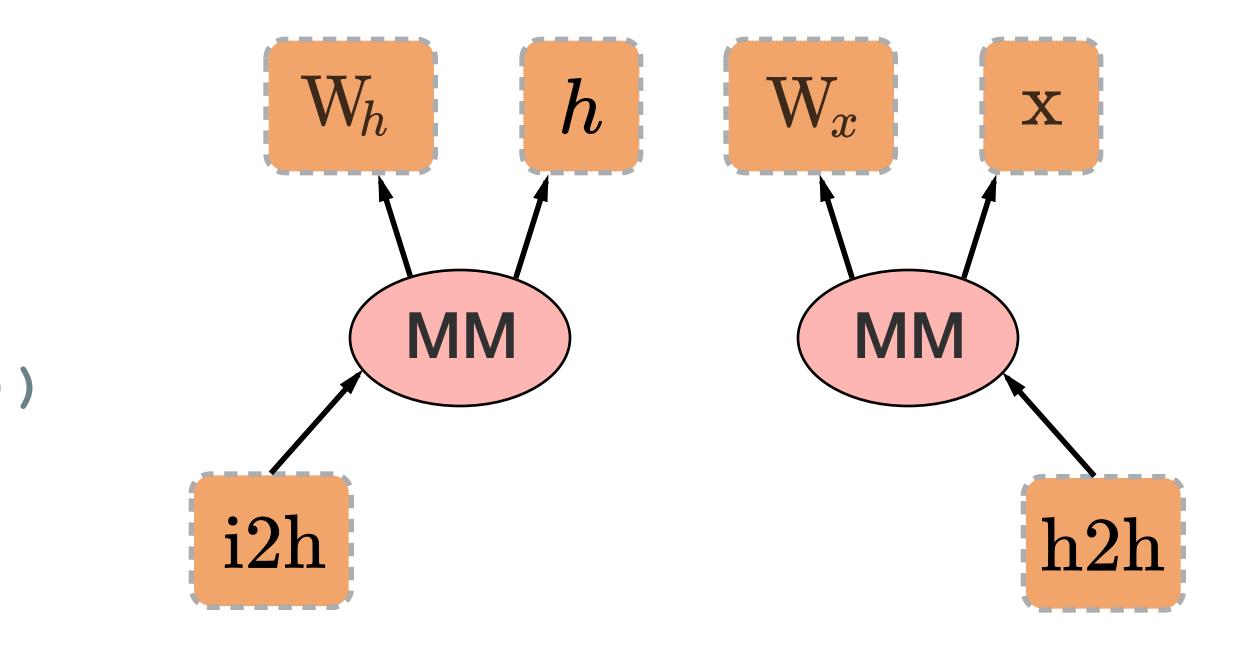
i2h = torch.mm(W\_x, x.t())
h2h = torch.mm(W\_h, prev\_h.t())



from torch.autograd import Variable

x = Variable(torch.randn(1, 10))
prev\_h = Variable(torch.randn(1, 20))
W\_h = Variable(torch.randn(20, 20))
W\_x = Variable(torch.randn(20, 10))

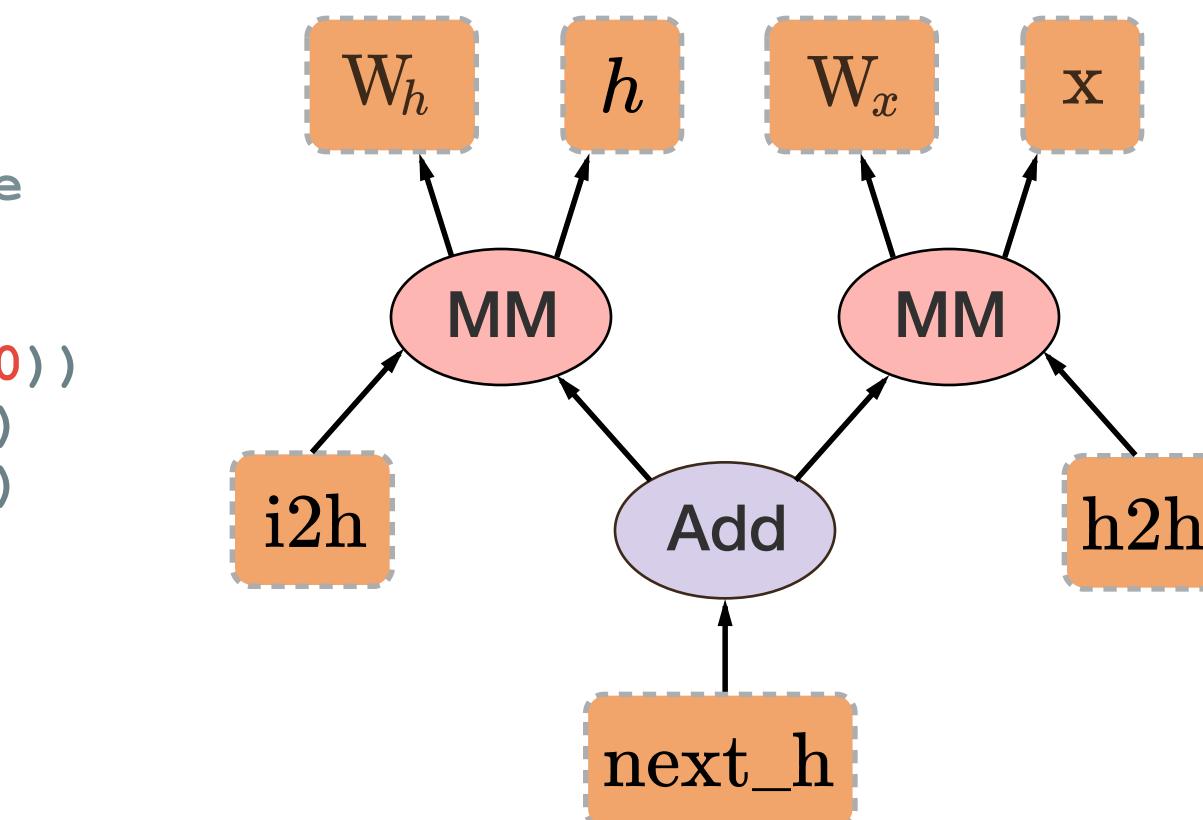
i2h = torch.mm(W\_x, x.t())
h2h = torch.mm(W\_h, prev\_h.t())
next\_h = i2h + h2h



from torch.autograd import Variable

x = Variable(torch.randn(1, 10))
prev\_h = Variable(torch.randn(1, 20))
W\_h = Variable(torch.randn(20, 20))
W\_x = Variable(torch.randn(20, 10))

i2h = torch.mm(W\_x, x.t())
h2h = torch.mm(W\_h, prev\_h.t())
next\_h = i2h + h2h

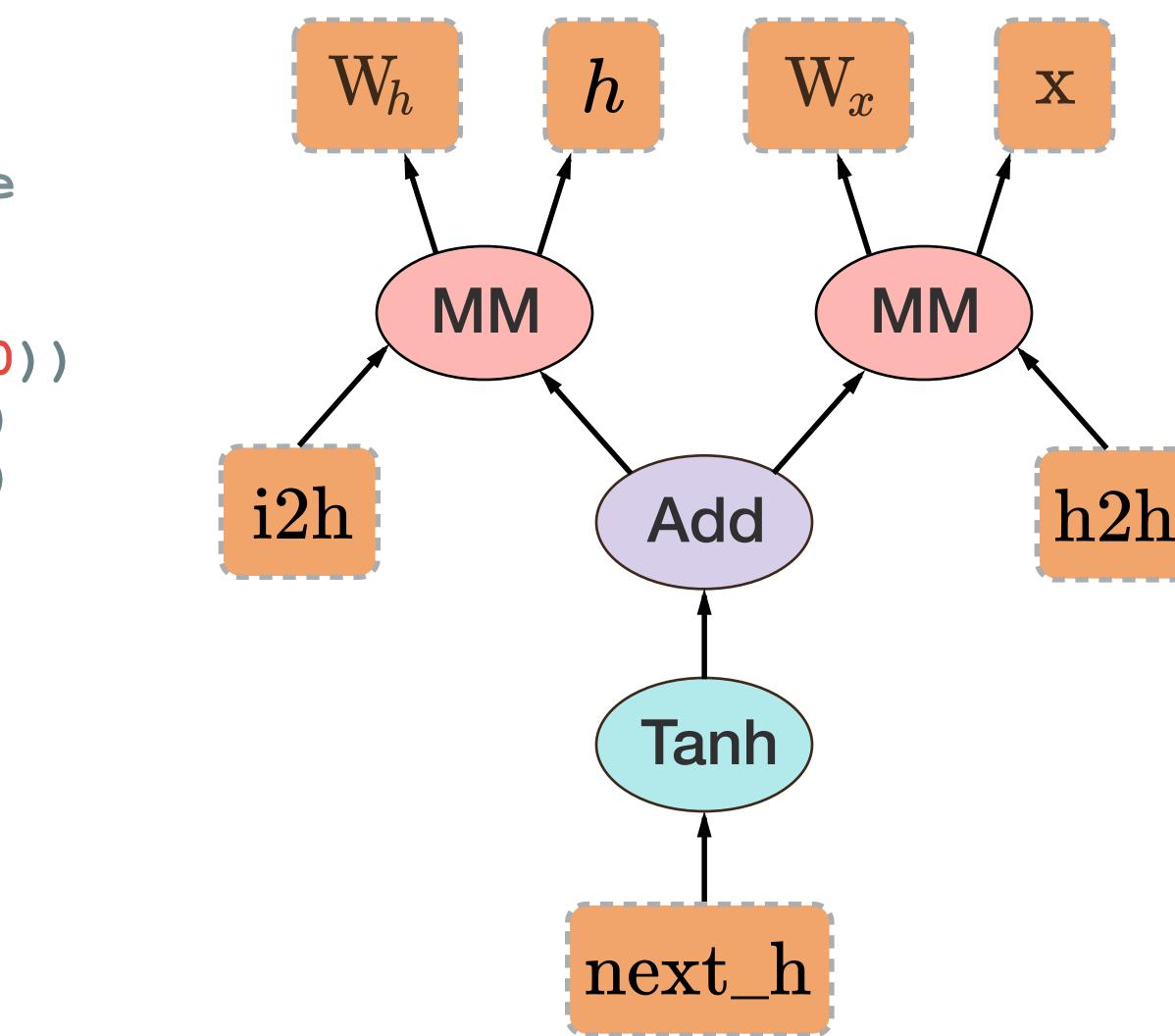




from torch.autograd import Variable

x = Variable(torch.randn(1, 10))
prev\_h = Variable(torch.randn(1, 20))
W\_h = Variable(torch.randn(20, 20))
W\_x = Variable(torch.randn(20, 10))

i2h = torch.mm(W\_x, x.t())
h2h = torch.mm(W\_h, prev\_h.t())
next\_h = i2h + h2h
next\_h = next\_h.tanh()



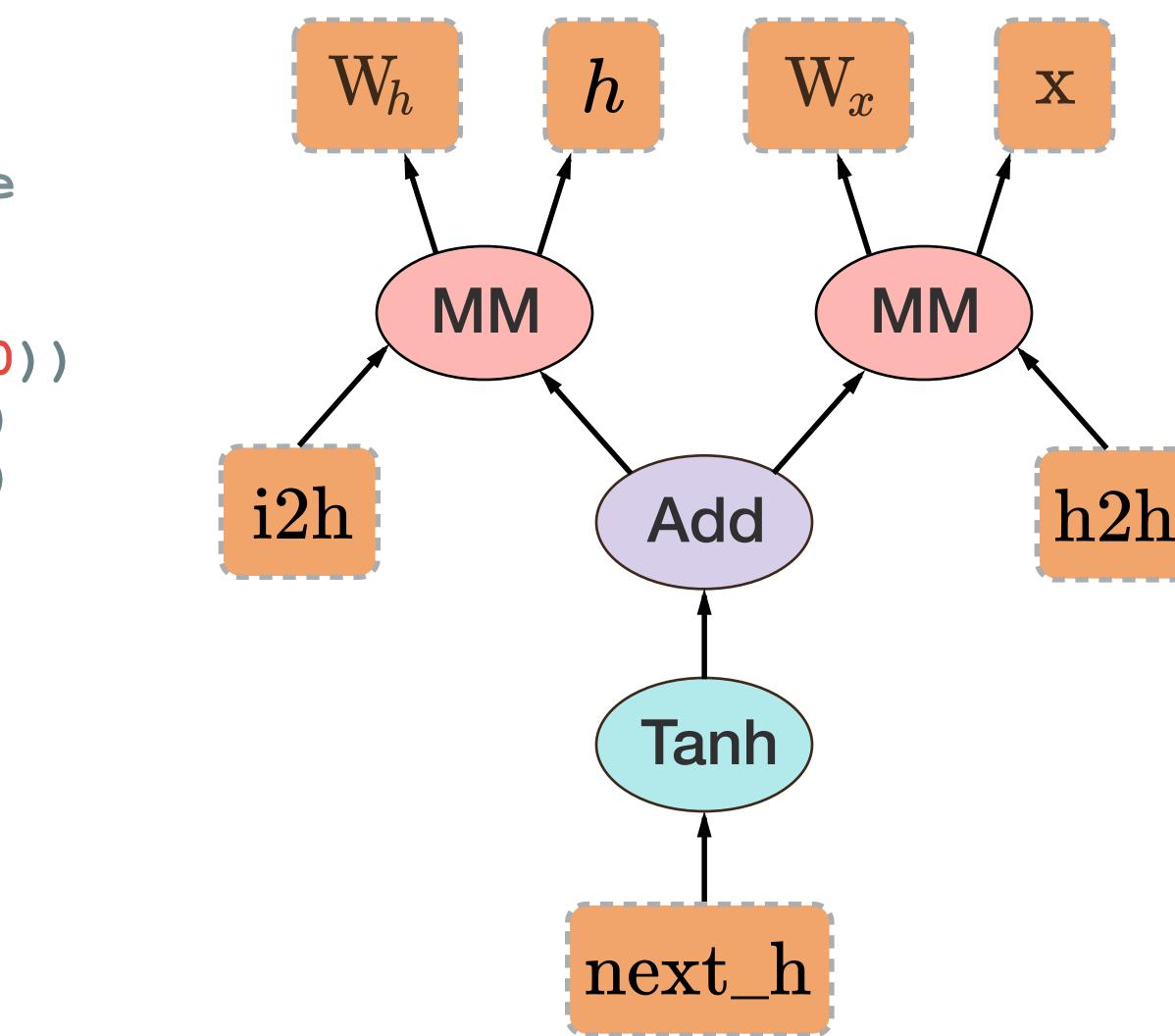


from torch.autograd import Variable

x = Variable(torch.randn(1, 10))
prev\_h = Variable(torch.randn(1, 20))
W\_h = Variable(torch.randn(20, 20))
W\_x = Variable(torch.randn(20, 10))

i2h = torch.mm(W\_x, x.t())
h2h = torch.mm(W\_h, prev\_h.t())
next\_h = i2h + h2h
next\_h = next\_h.tanh()

next\_h.backward(torch.ones(1, 20))





### PyTorch

- Naturally enables dynamic deep learning
- easy to interface with a wide range of interactive environments
- because of an imperative style of programming
- because of deep Python integration
- as fast as anything else out there on average

### PYTORCH facebook http://pytorch.org NSTITUT DES SCIENCES ET TECHNOLOGIE





























