

Noisy Dual Principal Component Pursuit

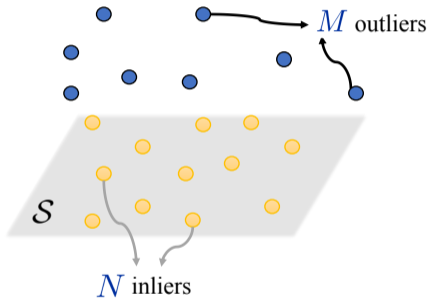
Tianyu Ding, Zihui Zhu, Tianjiao Ding, Yunchen Yang,
René Vidal, Manolis C. Tsakiris, Daniel P. Robinson

ICML 2019



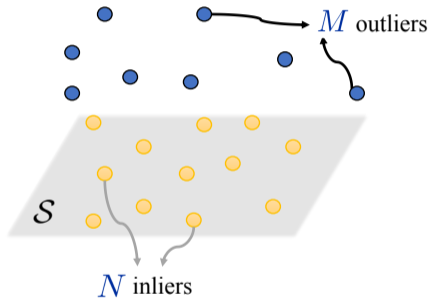
Motivation

Problem: learning a subspace from corrupted data



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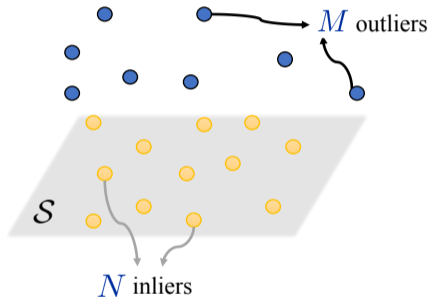
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- *Low relative dimension (d/D)*
 - Outlier Pursuit [Xu et al. 10]
 $M = O(N)$ outliers

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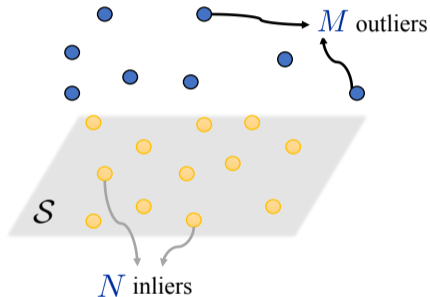
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 - DPCP [Tsakiris 15, Zhu 18]
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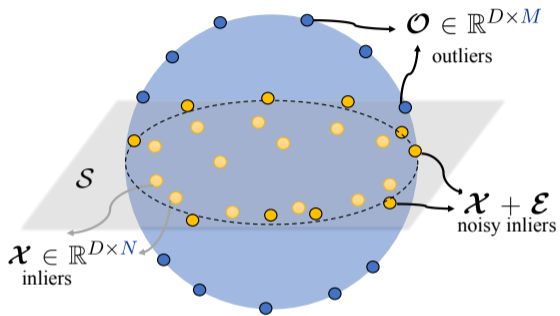


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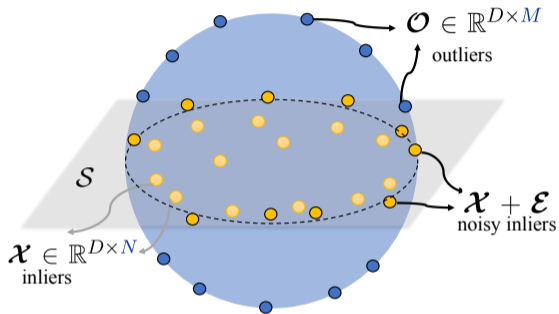
Focus of this paper

Robust subspace learning of high relative dimension with noisy data

Noisy Dual Principal Component Pursuit (DPCP)

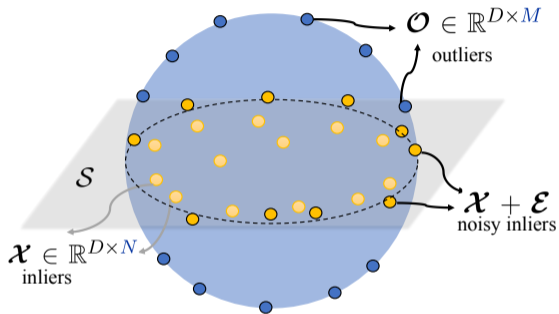


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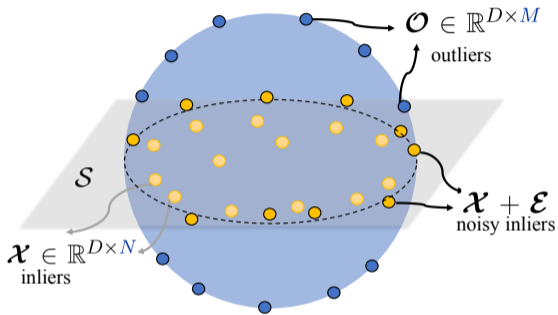
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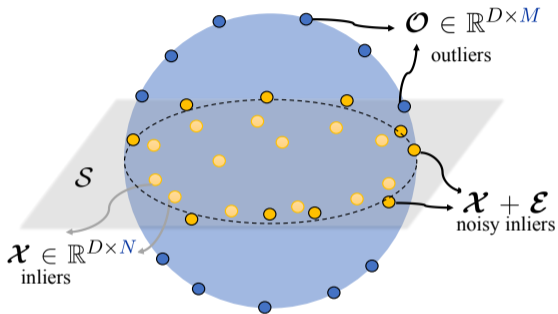
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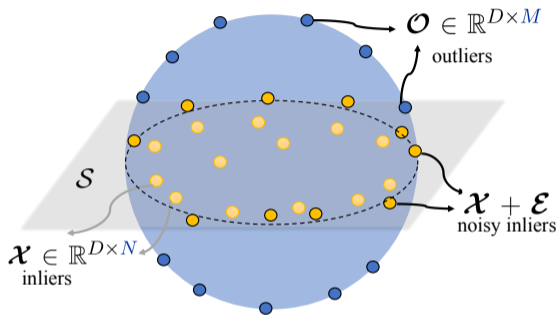
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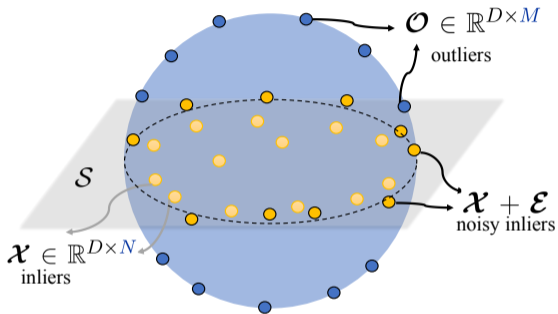
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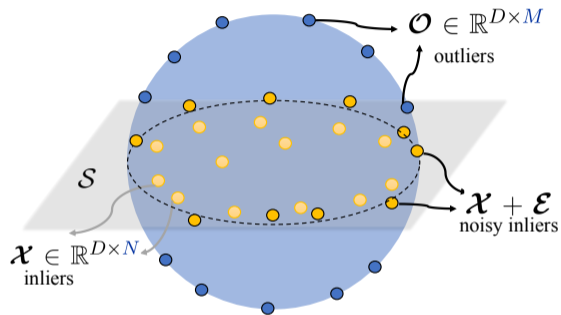
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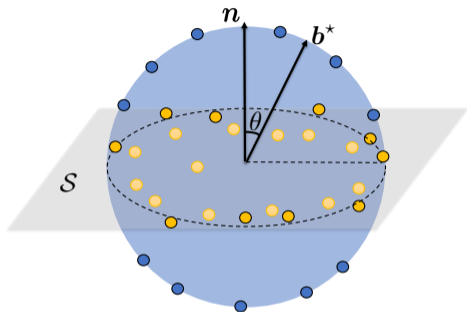


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DPCP problem formulation

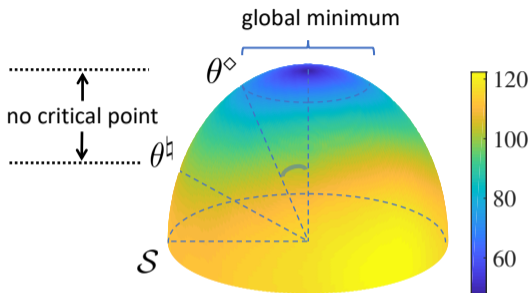
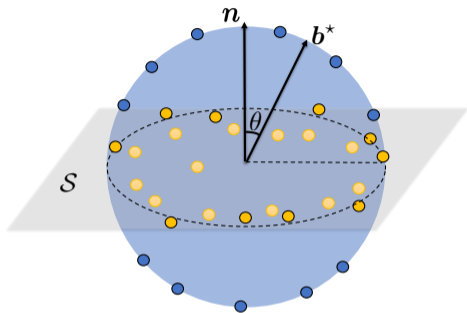
$$\min_b \|\tilde{\mathcal{X}}^\top \mathbf{b}\|_1 \quad \text{s.t.} \quad \|\mathbf{b}\|_2 = 1 \quad (1)$$

Deterministic Global Optimality Analysis



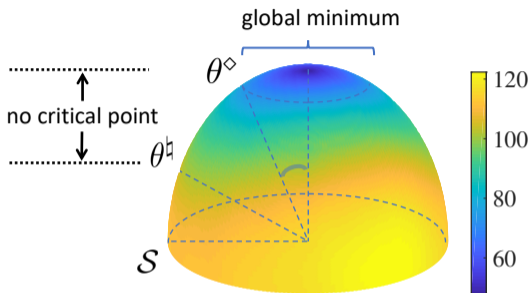
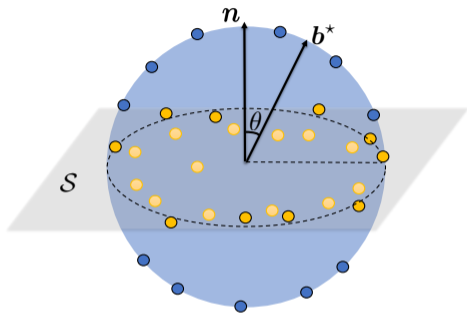
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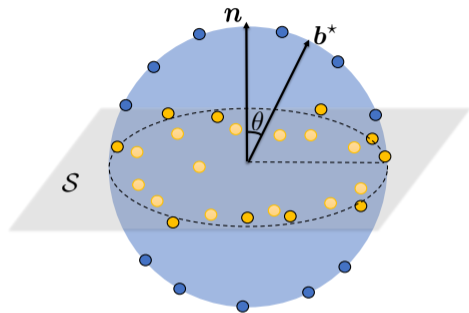
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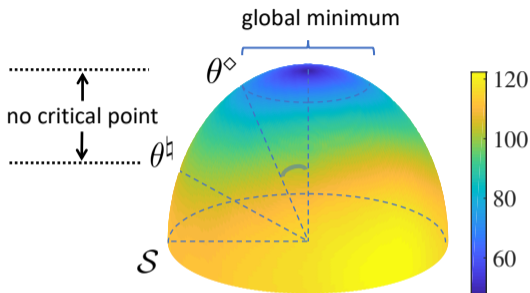
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- **Lemma:** critical point is close to n or is close to S

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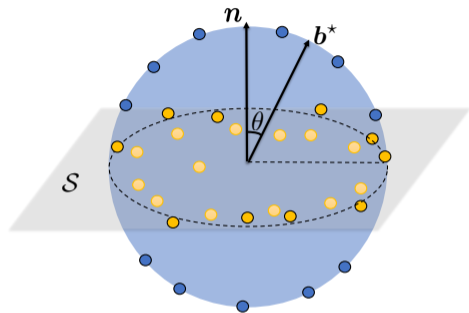
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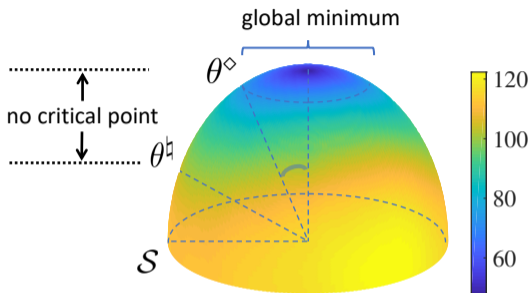
- **Lemma:** critical point is close to \mathbf{n} or is close to \mathcal{S}
- **Theorem:** \mathbf{b}^* is close to \mathbf{n} :

$$\sin(\theta^\diamond) \lesssim \frac{\text{noise level}}{1 - \text{outlier ratio}}$$

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- In the noiseless case, $b^* = n$

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with probability exceeding $1 - O(\frac{1}{N^2})$ if

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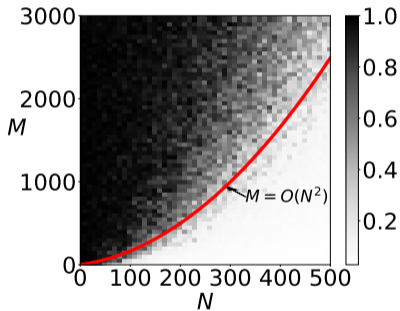
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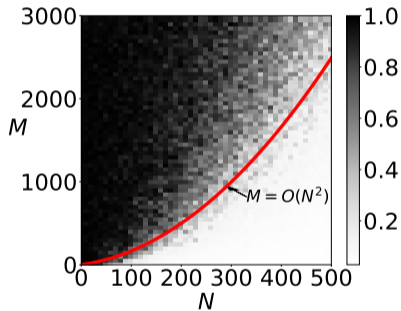
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- **Comparison with state-of-the-art:** other methods can only handle at most $M = O(N)$ outliers in theory [Lerman and Maunu 18]

Projected SubGradient Method (PSGM)

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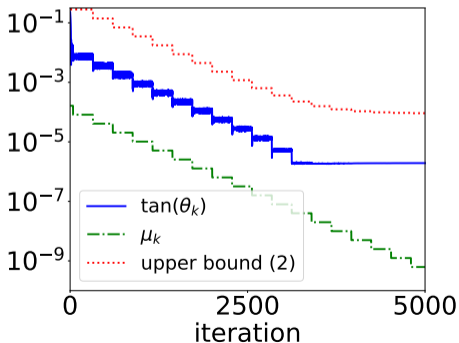
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Theorem

$\tan(\theta_k)$ has a **piecewise linear convergence rate**:

$$\tan(\theta_k) \lesssim \beta^{\lfloor (k-K_0)/K \rfloor} + \frac{\sqrt{\sigma}}{\sqrt{1-2\sqrt{\sigma}}}. \quad (2)$$



Experiments on 3D Point Cloud Road Data

Task

Learn an affine plane as a model for the road from a 3D point cloud

- Determine points that lie on the plane (inliers) / off the plane (outliers)
- Frame 328 of dataset KITTI-CITY-71, with inliers (blue) / outliers (red)



Contains around 10^5 points with approximately 50% outliers

Thank you!

Poster Session:

Today 06:30 – 09:00 PM
@ Pacific Ballroom #188