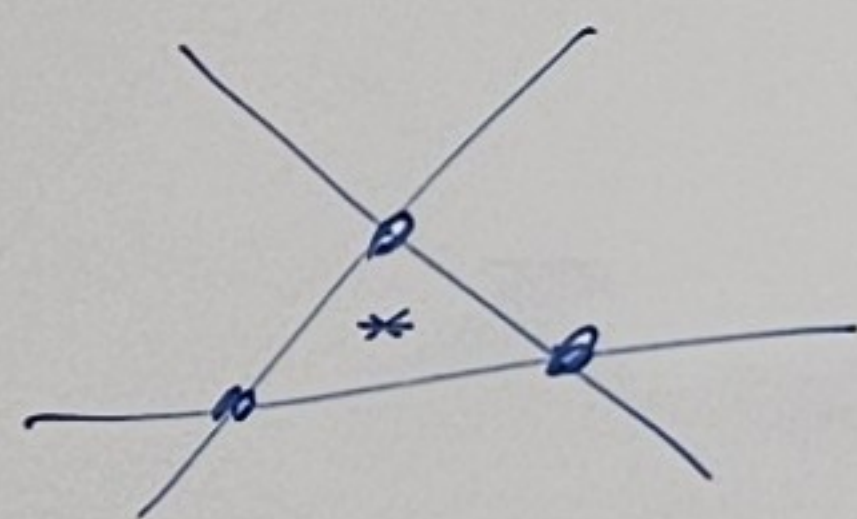


$$\begin{cases} 2x + 3y = 1 \\ x - 4y = -9 \\ 2x - y = -1 \end{cases}$$



$$\begin{bmatrix} 2 & 3 \\ 1 & -4 \\ 2 & -1 \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix} = \begin{bmatrix} 1 \\ -9 \\ -1 \end{bmatrix}$$

$$\textcircled{A} w = B \quad / \cdot A^{-1}$$

$$w = \textcircled{A^{-1}} B$$

np. linalg. inv

$A @ B$ $A.T$

$$Aw = B$$

$$\textcircled{A^T A} w = A^T B \quad / \cdot (A^T A)^{-1}$$

$$w = \textcircled{(A^T A)^{-1} A^T} B$$

1. w domu: dla $A_{M \times M}$
 $\textcircled{B} = \textcircled{A}$

2. w domu: wyprow.
 prawo-stronna odwrot.

$$(A^T)^T = A$$

$$(A \cdot B)^T = B^T A^T$$

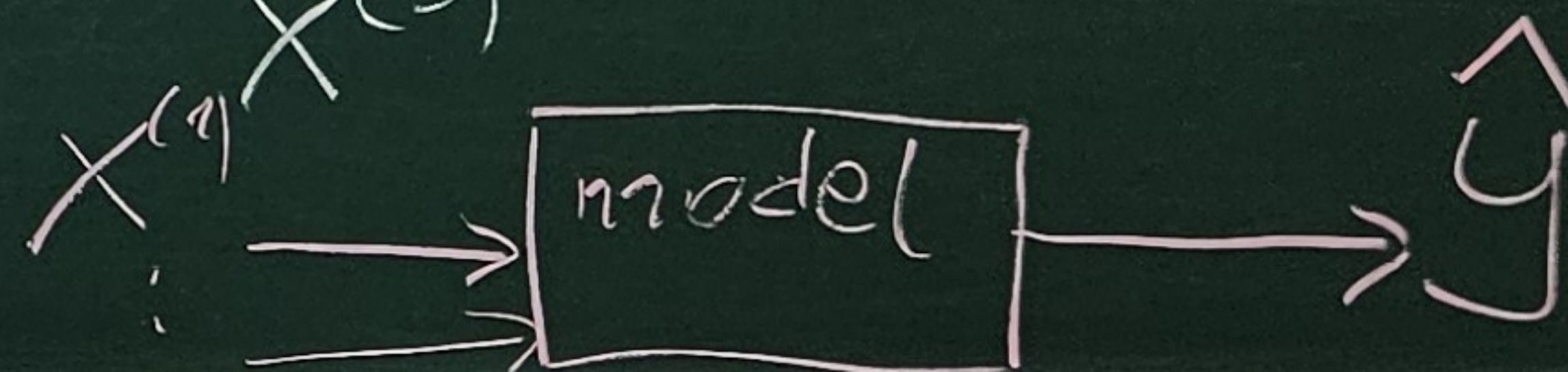
$$(A^{-1})^{-1} = A$$

$$(A \cdot B)^{-1} = B^{-1} A^{-1}$$

$$(A^T)^{-1} = (A^{-1})^T$$

$$(A \pm B)^T = A^T \pm B^T$$

~~$$(A \pm B)^{-1} = A^{-1} \pm B^{-1}$$~~



$$\left\{ \begin{bmatrix} x_i^{(1)} \\ \vdots \\ x_i^{(s)} \end{bmatrix}, y_i \right\}_{i=1}^N$$

$$y_i \in \mathbb{R} \quad - \text{regresja}$$

$$\hat{y} = \phi(x; \Theta) \quad \hat{y} = \phi_{\Theta}(x)$$

$$\{ \cancel{x}_i, y_i \}_{i=1}^N$$

$$X = \begin{bmatrix} x_1^{(1)} & x_2^{(1)} & \dots & x_N^{(1)} \\ \vdots & \vdots & & \vdots \\ x_1^{(s)} & x_2^{(s)} & \dots & x_N^{(s)} \end{bmatrix}$$

$$Y = [y_1 \quad y_2 \quad \dots \quad y_N]$$

$$\hat{Y} = [\hat{y}_1 \quad \hat{y}_2 \quad \dots \quad \hat{y}_N]$$

$$e = y - \hat{y}$$

$$e_i = y_i - \hat{y}_i$$

Dane: X^T, Y^T

X^T Szukane $\hat{\alpha}$

$$Y = \hat{\alpha}^T X$$

$$Y X^T = \hat{\alpha}^T (X X^T)$$

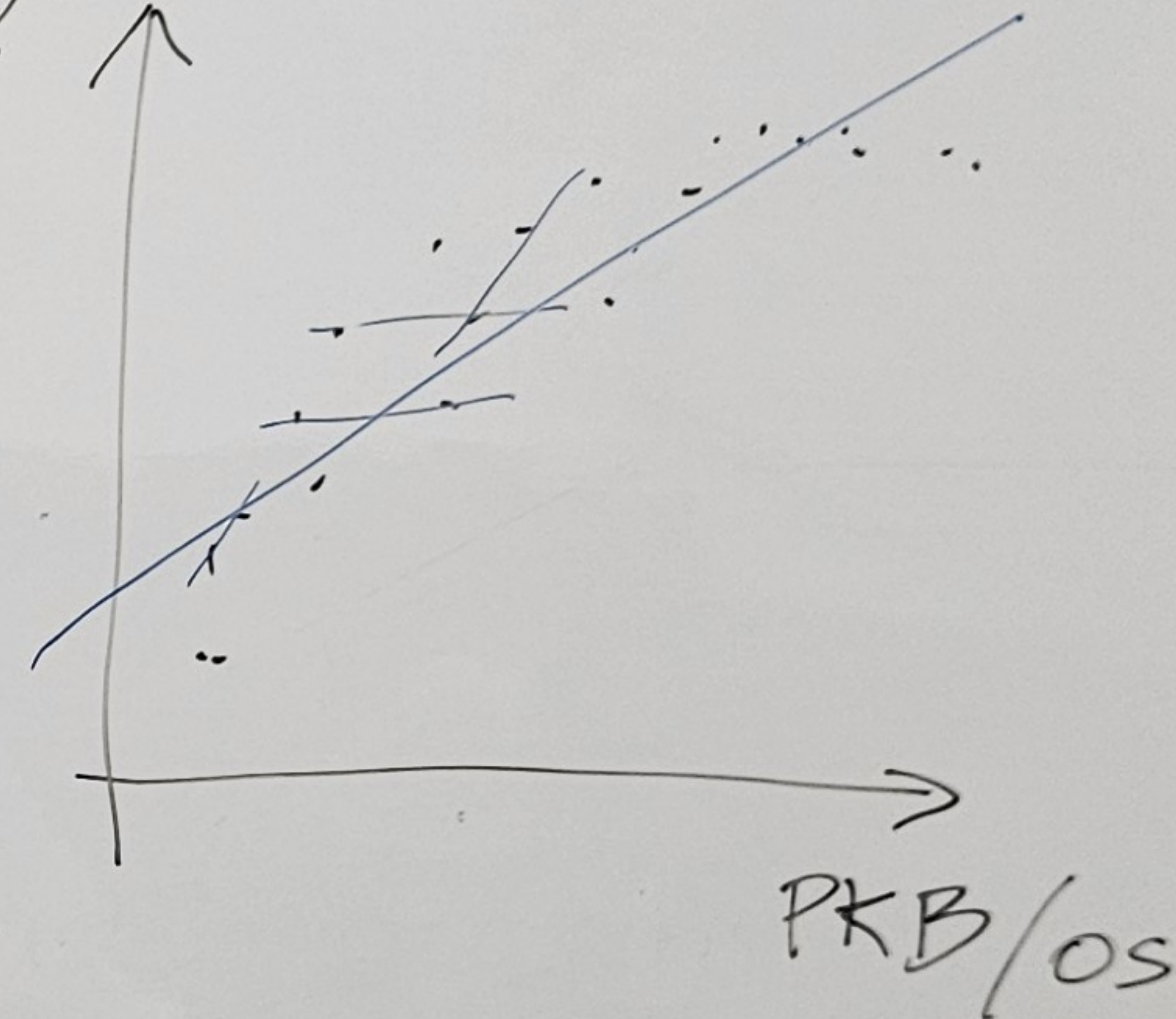
$$Y X^T (X X^T)^{-1} = \hat{\alpha}^T$$

$$\hat{\alpha} = (X X^T)^{-1} X Y^T$$

5×1

Aproksymacja średniokwadratowa.
Metoda najmn. kwadrat

poz. szcze



jak rozumieć
p-wartość?

$\frac{dF}{dx} \sim \frac{\partial F}{\partial x}$
Patryk
Nogaś

np.

$$\hat{y}_i = a_1 x_i^{(1)} + a_2 x_i^{(2)} + \dots + a_s x_i^{(s)} = \tilde{\Theta}^T x_i$$

$$\tilde{\Theta} = \begin{bmatrix} a_1 \\ \vdots \\ a_s \end{bmatrix}$$

$$\hat{Y} = \tilde{\Theta}^T X$$

$$\hat{Y} = [\tilde{\Theta}^T x_1 \quad \tilde{\Theta}^T x_2 \quad \dots \quad \tilde{\Theta}^T x_N] = \tilde{\Theta}^T [x_1 \quad x_2 \quad \dots \quad x_N]$$