

EECS 16A : Module 3 Last lecture.

Today.

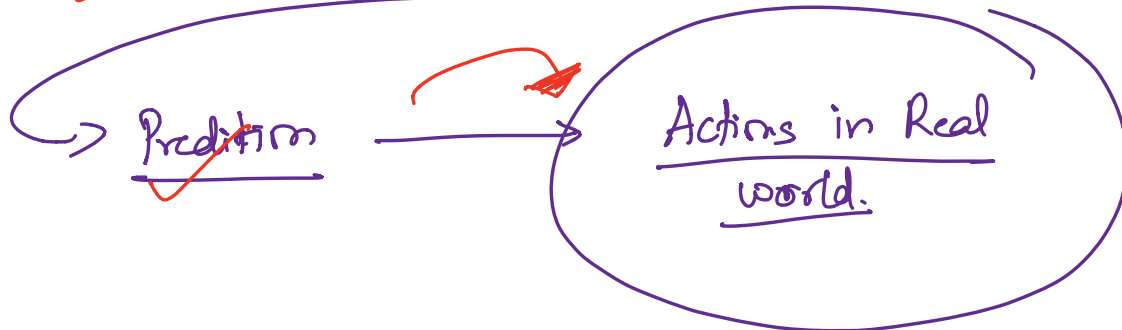
- GPS summary
- Course evaluations
- OMP.

Logistics

- Last lecture
- Please fill out survey.
- Thank your TAs.

Machine Learning -

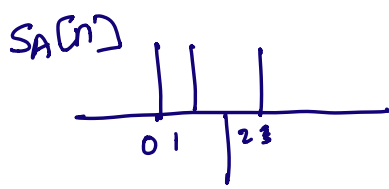
Real world data → Model → Evaluate



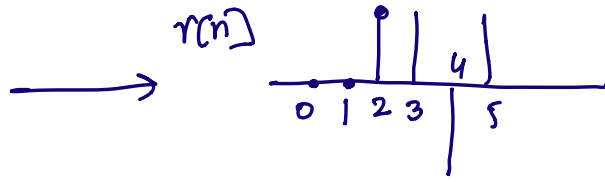
GPS

- ① identify which satellite is transmitting
- Delay / Shift

$$\vec{r} = \underbrace{\vec{s}_A}_{\text{signature A with shift } k_1}^{(k_1)} + \vec{s}_B^{(k_2)} + \vec{s}_D^{(k_3)} + \vec{n}$$



$$k_1 = 2$$



$$r[n] = \underline{\underline{s_A[n-2]}}$$

$$\left\{ \vec{r}[n] = \alpha_1 \vec{s}_A[n-k_1] + \alpha_2 \vec{s}_B[n-k_2] + \alpha_3 \vec{s}_D[n-k_3] + \vec{n} \right\}$$

$$\begin{bmatrix} | \\ \vec{r}[n] \\ | \end{bmatrix} = \begin{bmatrix} | & | & | & | \\ \vec{s}_A[n-k_1] & \vec{s}_B[n-k_2] & \vec{s}_C[n-k_0] & \vec{s}_D[n-k_3] \\ | & | & | & | \end{bmatrix} \begin{bmatrix} \alpha_1 \\ \alpha_2 \\ \alpha_3 \\ \circ \end{bmatrix}$$

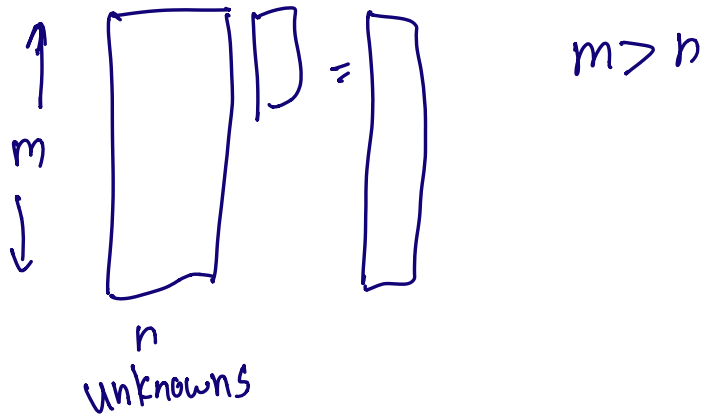
$$+ \vec{n}$$

② Delay / shift \rightarrow Distance

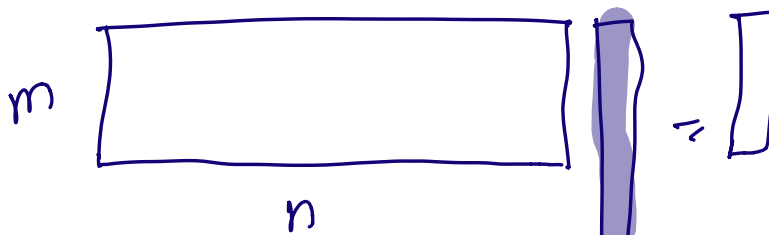
③ Trilateration : Distances \leftrightarrow Position

④ To handle noise: Least Squares.
"estimate of your position"

- Easy to have measurements > unknowns



Different scenario:



Solutions: {
 infinitely many.
 0 solutions if
 inconsistent.

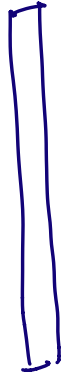
never unique solution.

$100 \times 100 \rightarrow 10^4 \rightarrow 10^4$ measurements

YES! Special cases we can solve:

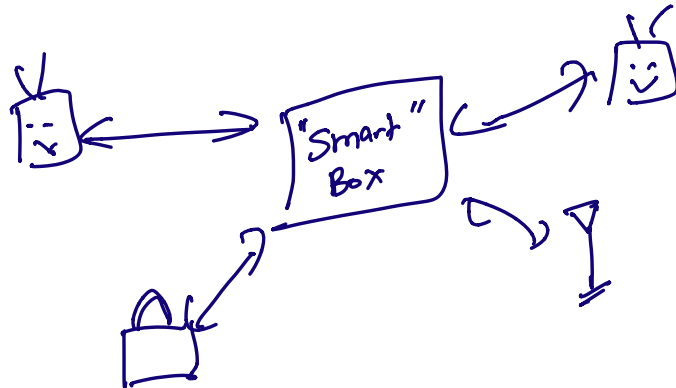
SPARSITY

SPARSITY :



→ most of the entries are 0

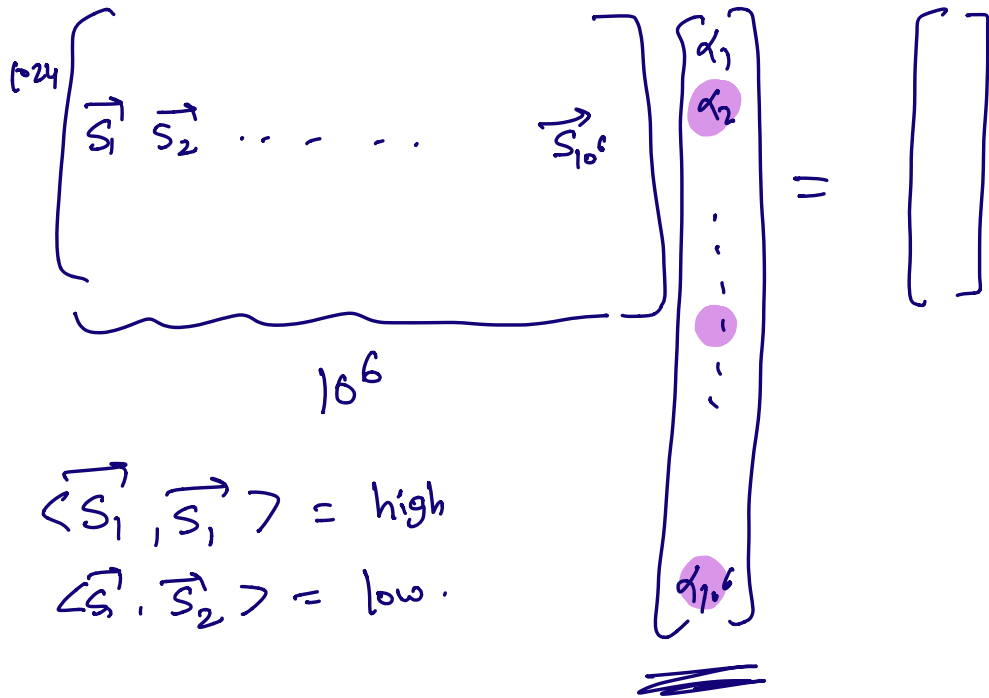
Internet of Things : millions of devices



\vec{s}_1 \vec{s}_2

\vec{s}_{10^6} . . .

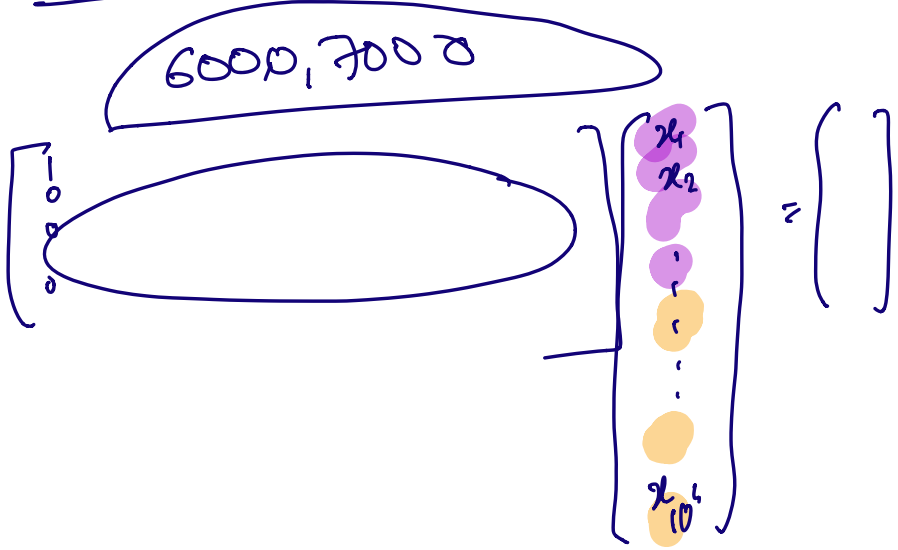
$$\vec{r} = \alpha_1 \vec{s}_1 + \alpha_2 \vec{s}_2 + \dots + \alpha_n \vec{s}_n \quad \text{Most of the devices}$$



Most entries are zero, some are non-zero!

SPARSE

Imaging $100 \times 100 = 10^4$ pixels



Office hours

$$\langle \vec{s}_A, \vec{s}_A \rangle = 1024$$

$$\langle \vec{s}_B, \vec{s}_A \rangle \approx 0$$

$$\vec{r} = \vec{s}_A + \frac{1}{2} \vec{s}_B$$

$$\langle \vec{r}, \vec{s}_A \rangle = \langle \vec{s}_A + \frac{1}{2} \vec{s}_B, \vec{s}_A \rangle.$$

$$= \langle \vec{s}_A, \vec{s}_A \rangle + \frac{1}{2} \langle \vec{s}_B, \vec{s}_A \rangle.$$

$$= 1024$$