

Regularization and Optimization is All You Need?

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<https://github.uio.no/larsbog/FYSSTK-Project1>

The basis for many data-driven methods is the optimization of numerical models to describe relations in data. With the increasing availability of large datasets and the growing complexity of models, there is an increasing need for efficient optimization techniques that can handle the computational challenges associated with big data. Furthermore, a good optimization metric can be crucial to find the best possible model to describe the data. In this paper different methods of such optimization are studied in the context of large datasets and big data with possibly noise-affected input data. To render the best possible fits a multitude of cost functions, minimization algorithms and other approaches to reduce the computation associated with the optimization process are studied and evaluated. Reducing the computational cost is also important to improve the economical and ecological footprint of training large models on big data, as the spread of data-driven methods in all areas of life is increasing rapidly. Using optimal optimization techniques the convergence can be improved by up to one order of magnitude.

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I. INTRODUCTION

Optimizing numerical models to model a set of data has been a challenge of the natural sciences for many decades. But with the introduction of artificial neural networks in all disciplines over the last years a special focus on those optimization techniques is relevant.

In this paper different methods of such optimization are studied in the context of large datasets and big data with possibly noise-affected input data. To render the best possible fits a multitude of cost functions, minimization algorithms and other approaches to reduce the computation associated with the optimization process are studied and evaluated. Reducing the computational cost

is also important to improve the economical and ecological footprint of training large models on big data, as the use of data-driven methods in all areas of life is increasing rapidly. To measure the possible improvements with state-of-the-art methods, the duration of optimization and the quality of the fit are evaluated. Assuming constant power consumption of the hardware, a reduction in computation time directly translates to a reduction in energy consumption and thus a smaller ecological and economical footprint.

In a first step, the dependence of the bias-variance tradeoff on the number of degrees of freedom in a model is studied. For this purpose, polynomial models of different degrees are fitted to data generated from the Runge function with significant noise. The results are then compared to different Ridge and Lasso models to study the effect of regularization on the bias-variance tradeoff. In the context of big data, the performance of different numerical minimization algorithms is studied. For this purpose, the performance of gradient descent, stochastic gradient descent and different optimization algorithms such as Adam are compared in the context of Ridge and Lasso regression. Furthermore, the possible advantages and disadvantages of stochastic gradient descent techniques are evaluated. Finally, the effect of resampling methods such as bootstrapping and k-fold cross-validation on the bias-variance tradeoff is studied.

In the following section the theoretical background of the methods used in this paper is presented. In section II the implementation of these methods is discussed. The results of applying these methods to different datasets are presented in section III. Finally, a conclusion is drawn in section IV and an outlook on possible future work is given in section V.

II. METHODS

A. Theoretical Background

To find the optimal solution to a linear model in the form

$$X\vec{\theta} = \vec{y}, \quad X \in \mathbb{R}^{n \times p}, \vec{y} \in \mathbb{R}^n, \vec{\theta} \in \mathbb{R}^p, \quad (1)$$

the ordinary least squares (OLS) method can be used. The OLS method minimizes the squared deviation between the model prediction and the actual data (Hastie *et al.*, 2009). This is done by minimizing the cost function

$$C_{\text{OLS}}(\vec{\theta}) = \frac{1}{n} \|X\vec{\theta} - \vec{y}\|_2^2. \quad (2)$$

This method has been widely used in the past ultimately also because it has an analytical solution in the case that the matrix product $X^T X$ is invertible, i.e. $\det(X^T X) \neq 0$. In this case the optimal parameters $\vec{\theta}_{\text{OLS}}$ can be found by solving the normal equations (Elstner and Kubar, 2025; Hastie *et al.*, 2009)

$$\vec{\theta}_{\text{OLS}} = (X^T X)^{-1} X^T \vec{y}. \quad (3)$$

Taking the derivative of the cost function in eq. (2) with respect to the parameters $\vec{\theta}$ and inserting the solution in eq. (3) shows that this is indeed a minimum of the cost function:

$$\left. \frac{\partial C_{\text{OLS}}}{\partial \vec{\theta}} \right|_{\vec{\theta}_{\text{OLS}}} = \frac{2}{n} X^T (X\vec{\theta} - \vec{y}) \Big|_{\vec{\theta}_{\text{OLS}}} = 0. \quad (4)$$

1. Bias-Variance Tradeoff and Regularization

The cost function of the ordinary least squares method can also be identified as the mean squared error (MSE) between the model prediction and the actual data

$$\text{MSE}(\vec{y}, \vec{\tilde{y}}) = \frac{1}{n} \sum_{i=0}^{n-1} (y_i - \tilde{y}_i)^2 = \mathbb{E}[(y - \tilde{y})^2], \quad (5)$$

where $\vec{\tilde{y}} = X\vec{\theta}$ is the model prediction. $\mathbb{E}$ denotes the expectation value. The MSE can be decomposed into three components, the squared bias, the variance and the irreducible error σ^2 as (Bishop, 2006; Hastie *et al.*, 2009)

$$\text{MSE}(\vec{y}, \vec{\tilde{y}}) = \text{Bias}^2(\vec{y}, \vec{\tilde{y}}) + \text{Var}(\vec{\tilde{y}}) + \sigma^2, \quad (6)$$

where the bias is defined as

$$\text{Bias}(\vec{y}, \vec{\tilde{y}}) = \mathbb{E}[\vec{\tilde{y}}] - \vec{y}, \quad (7)$$

and the variance as

$$\text{Var}(\vec{\tilde{y}}) = \mathbb{E}[(\vec{\tilde{y}} - \mathbb{E}[\vec{\tilde{y}}])^2]. \quad (8)$$

The irreducible error σ^2 is the variance of the noise in the data and cannot be reduced by any model. The bias-variance decomposition in eq. (6) shows that there is a tradeoff between bias and variance when trying to minimize the MSE. A model with low complexity will have a high bias but low variance, while a model with high complexity will have a low bias but high variance. This is known as the bias-variance tradeoff. The OLS method can lead to overfitting of the data, especially when the number of parameters p is large compared to the number of data points n . In this case, the model will fit the noise in the data rather than the underlying trend, leading to a low bias but high variance. On the contrary, a model with too few parameters will not be able to capture the underlying trend in the data, leading to a high bias but low variance (Elstner and Kubar, 2025; Hastie *et al.*, 2009). To mitigate the effects of overfitting, regularization techniques such as Ridge and Lasso regression can be used. These techniques add a penalty term to the cost function that penalizes large values of the parameters $\vec{\theta}$ (Lekhansh, 2024). The cost function for Ridge regression is given by

$$C_{\text{Ridge}}(\vec{\theta}) = \frac{1}{n} \|X\vec{\theta} - \vec{y}\|_2^2 + \lambda \|\vec{\theta}\|_2^2, \quad (9)$$

where λ is the regularization parameter that controls the strength of the penalty term. The cost function for Lasso regression is given by

$$C_{\text{Lasso}}(\vec{\theta}) = \frac{1}{n} \|X\vec{\theta} - \vec{y}\|_2^2 + \lambda \|\vec{\theta}\|_1, \quad (10)$$

where the L_1 norm is defined as $\|\vec{\theta}\|_1 = \sum_{i=0}^{p-1} |\theta_i|$ (Elstner and Kubar, 2025; Lekhansh, 2024). Both Ridge and Lasso regression can help to reduce the variance of the model by penalizing large values of the parameters $\vec{\theta}$, leading to a different bias-variance tradeoff. For Ridge regression, we can derive the effective number of parameters also called degrees of freedom as (Hastie *et al.*, 2009)

$$n_{\text{effective}} = \sum_{i=1}^{n_{\text{features}}} \frac{d_i^2}{d_i^2 + \lambda}, \quad (11)$$

where d_i are the singular values of the design matrix X . Thus, regularization effectively reduces the number of parameters in the model, leading to a bias-variance tradeoff that can be tuned by the regularization parameter λ . While OLS models can be analytically optimized using eq. (3) for the case where $X^T X$ is invertible, the same is true for Ridge regression in the case where $X^T X + \lambda I$ is invertible. The optimal parameters for Ridge regression can be found by solving the modified normal equations (Elstner and Kubar, 2025)

$$\vec{\theta}_{\text{Ridge}} = (X^T X + \lambda I)^{-1} X^T \vec{y}. \quad (12)$$

2. Numerical Optimization

However, for Lasso regression there is no analytical solution and numerical methods must be used to obtain the

optimal parameters $\vec{\theta}_{\text{Lasso}}$. All numerical optimization methods are based on the idea of iteratively minimizing the cost function. Around the current guess for the parameters $\vec{\theta}_i$ the cost function can be approximated by a Taylor expansion as (Hastie *et al.*, 2009)

$$\begin{aligned} C_{\text{OLS}}(\vec{\theta}) &= C_{\text{OLS}}(\vec{\theta}_i) + \nabla C_{\text{OLS}}(\vec{\theta}_i)^T (\vec{\theta} - \vec{\theta}_i) \\ &+ \frac{1}{2} (\vec{\theta} - \vec{\theta}_i)^T H(\vec{\theta}_i) (\vec{\theta} - \vec{\theta}_i) \\ &+ \mathcal{O}\left(\left\|\vec{\theta} - \vec{\theta}_i\right\|_2^3\right), \end{aligned} \quad (13)$$

where $\nabla C_{\text{OLS}}(\vec{\theta}_i)$ is the gradient and $H(\vec{\theta}_i)$ the Hessian of the cost function at the current guess $\vec{\theta}_i$. Based on this approximation, the next guess for the parameters can be found by minimizing the quadratic approximation of the cost function. Since the calculation of the Hessian is computationally expensive, it is often neglected in practice. This leads to the gradient descent algorithm, where the next guess for the parameters is given by (Goodfellow *et al.*, 2016)

$$\vec{\theta}_{i+1} = \vec{\theta}_i - \eta \nabla C_{\text{OLS}}(\vec{\theta}_i), \quad (14)$$

where η is the learning rate that controls the step size of the update. The gradient descent algorithm can be further improved by using techniques such as momentum, Adagrad, RMSProp and Adam. These techniques adapt the learning rate based on the history of the gradients, leading to faster convergence and better performance.

a. Momentum in Gradient Descent The momentum technique in gradient descent helps to accelerate the convergence of the optimization process by adding a fraction of the previous update to the current update. This helps to smooth out the updates and reduces oscillations in the optimization process. The update rule for gradient descent with momentum is given by

$$\begin{aligned} v_i &= \delta \cdot \left(\theta_i - \theta_{i-1} - \eta \nabla C_{\text{OLS}}(\vec{\theta}_i) \right) \\ \vec{\theta}_{i+1} &= \vec{\theta}_i + v_i, \end{aligned} \quad (15)$$

where v_i is the velocity vector that accumulates the gradients, β is a hyperparameter that controls the decay rate of the velocity, and the other symbols have the same meaning as in the gradient descent update rule (noa, 2025; Goodfellow *et al.*, 2016).

b. Adagrad The Adagrad algorithm adapts the learning rate for each parameter based on the history of the gradients. The update rule for Adagrad is given by

$$\begin{aligned} g_i &= g_{i-1} + \nabla C_{\text{OLS}}(\vec{\theta}_i) \odot \nabla C_{\text{OLS}}(\vec{\theta}_i), \\ \vec{\theta}_{i+1} &= \vec{\theta}_i - \frac{\eta}{\sqrt{g_i + \epsilon}} \odot \nabla C_{\text{OLS}}(\vec{\theta}_i), \end{aligned} \quad (16)$$

where g_i is the accumulated squared gradient, $\odot$ denotes the element-wise product and ϵ is a small constant to prevent division by zero (noa, 2025; Goodfellow *et al.*, 2016).

c. RMSProp The RMSProp algorithm is a modification of Adagrad that aims to reduce its aggressive, monotonically decreasing learning rate. It does this by maintaining a moving average of the squared gradients, which allows it to adapt the learning rate for each parameter more effectively. The update rule for RMSProp is given by

$$\begin{aligned} s_i &= \beta s_{i-1} + (1 - \beta) \nabla C_{\text{OLS}}(\vec{\theta}_i) \odot \nabla C_{\text{OLS}}(\vec{\theta}_i), \\ \vec{\theta}_{i+1} &= \vec{\theta}_i - \frac{\eta}{\sqrt{s_i + \epsilon}} \odot \nabla C_{\text{OLS}}(\vec{\theta}_i), \end{aligned} \quad (17)$$

where s_i is the moving average of the squared gradients, β is a hyperparameter that controls the decay rate of the moving average, and the other symbols have the same meaning as in the Adagrad update rule (noa, 2025; Goodfellow *et al.*, 2016).

d. Adam The Adam (Adaptive Moment Estimation) algorithm combines the ideas of momentum and RMSProp. It maintains a moving average of both the gradients and the squared gradients, allowing it to adapt the learning rate for each parameter based on both the first and second moments of the gradients. The update rule for Adam is given by

$$\begin{aligned} m_i &= \beta_1 m_{i-1} + (1 - \beta_1) \nabla C_{\text{OLS}}(\vec{\theta}_i), \\ s_i &= \beta_2 s_{i-1} + (1 - \beta_2) \nabla C_{\text{OLS}}(\vec{\theta}_i) \odot \nabla C_{\text{OLS}}(\vec{\theta}_i), \\ \vec{\theta}_{i+1} &= \vec{\theta}_i - \frac{\eta}{\sqrt{s_i + \epsilon}} \odot m_i, \end{aligned} \quad (18)$$

where m_i is the moving average of the gradients, s_i is the moving average of the squared gradients, β_1 and β_2 are hyperparameters that control the decay rates of the moving averages, and the other symbols have the same meaning as in the previous update rules (noa, 2025; Goodfellow *et al.*, 2016).

3. Stochastic Gradient Descent

As the computation of the gradient $\nabla C_{\text{OLS}}(\vec{\theta}_i)$ can be computationally expensive, especially for large datasets, a common approach is to use stochastic gradient descent (SGD). In SGD, the gradient is approximated by calculating it on a small subset of the data, called a mini-batch. This leads to a noisy estimate of the gradient, but it can significantly reduce the computational cost of each update step. The main challenge with SGD is to choose an appropriate mini-batch size. A small mini-batch size leads to a noisy estimate of the gradient, which can slow down convergence. On the other hand, a large mini-batch size can diminish the benefits of using SGD, as it

approaches the full gradient descent computation cost. In practice the optimal mini-batch size depends on the specific problem and dataset (Elstner and Kubar, 2025; Goodfellow *et al.*, 2016).

While the high variance of models with a high number of parameters can be counteracted with a large amount of data, the computational cost of fitting such models can become very high. This is especially relevant in the context of big data, where datasets can contain millions or even billions of samples. In such cases, it can be infeasible to use optimization algorithms that require the computation of the gradient over the entire dataset, such as ordinary gradient descent. For a dataset with N_{train} samples and a model with p parameters, the computational cost of calculating the gradient

$$\nabla_{\theta} C_{\text{OLS}} = \frac{2}{N} (X^T X \vec{\theta} - X^T \vec{y}), \quad (19)$$

is of order $\mathcal{O}(Np^2)$, as the matrix-vector products $X^T X$ needs to be computed. For very large datasets this can lead to very long computation times, as the entire dataset needs to be processed to compute the gradient. A common approach to counteract this problem is to use stochastic gradient descent (SGD) or mini-batch gradient descent, where the gradient is computed over a small subset of the data, called a batch. This leads to a significant reduction in computational cost, as the gradient can be computed in $\mathcal{O}(Bp^2)$, where B is the batch size. However, this comes at the cost of increased variance in the gradient estimate, as the gradient is only computed over a small subset of the data. This can lead to slower convergence and more oscillations in the optimization process.

While the decrease in computation time is significant, the result is even less black and white, when taking a closer look at the details. While conventional GD can benefit largely by precomputing the matrix products $X^T X$ and $X^T \vec{y}$, this is not possible for SGD, as the batches change in every epoch. This leads to a significant increase in computation time per epoch for SGD compared to GD. However, as the number of epochs needed to reach convergence is usually much lower for SGD than for GD, the overall computation time can still be significantly lower for SGD. This is especially relevant for very large datasets, where the computational cost of GD can become prohibitive. Because while GD needs to process the entire dataset and thus the computational cost is of order $\mathcal{O}(Np^2)$, SGD only needs to process a small batch of size B and thus the computational cost is of order $\mathcal{O}(Bp^2)$ and invariant of the size of the dataset, given the batch size is large enough to estimate the complete gradient well enough. This leads to a significant reduction in computation time for very large datasets, as the computational cost of SGD does not increase with the size of the dataset (Goodfellow *et al.*, 2016).

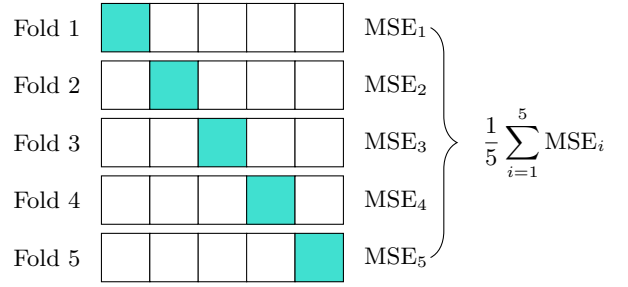


Figure 1 Illustration of 5-fold cross-validation. Each row corresponds to one fold: the turquoise block marks the held-out test set while the white blocks form the training set. The models’ error MSE_i is computed for each fold, and the final performance is the average of all MSE_i .

4. Resampling Methods

To better understand the performance of a model, e.g. in terms of the bias-variance tradeoff, resampling methods such as bootstrapping and k-fold cross-validation can be used. These methods allow to estimate the performance of a model on unseen data by repeatedly splitting the data into training and test sets.

a. Bootstrapping In bootstrapping, multiple datasets are generated by randomly sampling the original training dataset with replacement. Each of these datasets is then used to train a model, and the performance of the model is evaluated on the unmodified test dataset. This process is repeated multiple times, and the performance metrics are averaged to obtain an estimate of the model’s performance. Bootstrapping can be used to estimate the bias and variance of a model by analyzing the distribution of the performance metrics across the different bootstrap samples (Hastie *et al.*, 2009). The number of bootstrap samples is arbitrary, but a thousand samples are used in this work.

b. k-Fold Cross-Validation In k-fold cross-validation, the original dataset is divided into k equally sized folds. The model is then trained on $k - 1$ folds and evaluated on the remaining fold. This process is repeated k times, with each fold being used as the test set once. The performance metrics are then averaged across the k iterations to obtain an estimate of the model’s performance (Elstner and Kubar, 2025). The process of k-fold cross-validation is illustrated in fig. 1. For this work $k = 5$ folds are used.

B. Software Tools and Implementation

1. Programming Language and Libraries

The methods described in the previous section have been implemented in Python. The implementation is

structured in a modular way, allowing to easily switch between different optimization algorithms and resampling methods. The code is available on GitHub at <https://github.uio.no/larsbog/FYSSTK-Project1>. The following libraries have been used in the implementation:

numpy (Harris *et al.*, 2020) It is a fundamental package for scientific computing in Python. It provides support for large, multidimensional arrays and matrices, along with a collection of mathematical functions to operate on these arrays efficiently. It is used in this project for all matrix and vector operations, as well as for generating random numbers and performing statistical calculations.

scikit-learn (Pedregosa *et al.*, 2011) It is a machine learning library for Python that provides simple and efficient tools for data mining and data analysis. It includes implementations of various machine learning techniques, like data manipulation and performance evaluation metrics. It is used in this project for rescaling the data, splitting the data into training and test sets, and for implementing the resampling methods. Furthermore, it provides the implementation of the mean squared error (MSE) metric used to evaluate the performance of the models.

matplotlib (Hunter, 2007) It is a plotting library for Python that provides a wide range of tools for creating different types of plots and visualizations. It is used in this project to visualize the results of the different methods and to create plots for the report.

2. Other Software Tools

The code has been developed using the **Visual Studio Code** editor, which provides a wide range of features for Python development, including syntax highlighting, code completion, and debugging tools. The version control system **Git** has been used to manage the codebase and track changes. The Large Language Model (LLM) **GitHub Copilot** has been used to assist in the development of the code by providing code suggestions and autocompletions based on the context of the code being written. All LLM-generated code has been reviewed and modified as necessary to ensure its correctness and suitability for the project. The LLM ChatGPT-4 has been used to create fig. 1. The LaTeX package **TikZ** has been used to create the figure. The LLM has been prompted to generate the TikZ code for the figure, which has then been modified as necessary to ensure its correctness and suitability for the report. The conversation can be found at the root of the GitHub repository.

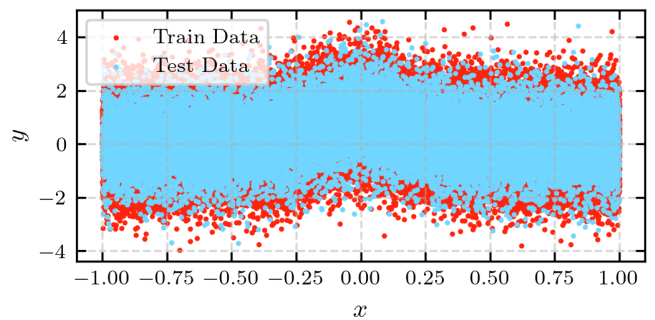


Figure 2 Scatter plot of the synthetic dataset generated using the Runge function with added Gaussian noise. The blue dots represent the test dataset, while the red dots represent the training dataset.

3. Implementation Details

To evaluate the performance of the different methods, a synthetic dataset has been generated using the Runge function. The Runge function is defined as

$$f(x) = \frac{1}{1 + 25x^2}, \quad x \in [-1, 1]. \quad (20)$$

The x -values are sampled uniformly in the interval $[-1, 1]$, and the corresponding y -values are generated by adding Gaussian noise with mean 0 and standard deviation $\sigma = 1$, unless otherwise specified. A visualization of the generated dataset is shown in fig. 2. The large amount of noise relative to the domain of $f(x)$ poses a critical challenge to all the models used, as the relation between output and features would otherwise be quite simple for ordinary methods. On the other hand the large amount of noise still allows to derive an optimal parametrization of the model, as the Central Limit Theorem ensures that the mean of the noise converges to zero for large datasets. This allows for a study of big data scenarios, in the limit of simple underlying relations. To evaluate the performance in dependence of the degrees of freedom, the x -values are expanded into multiple polynomial features up to a specified degree: $X_i = \{x_i^0, x_i^1, \dots, x_i^p\}$. All features and outputs are then rescaled to have zero mean and unit variance using the **StandardScaler** from **scikit-learn**. The mean and variance of the training data are used for rescaling the test data to avoid data leakage. There are analytical implementations of the OLS and Ridge regression methods, as described in eq. (3) and eq. (12). Furthermore, numerical optimizers are implemented from scratch based on a class inheritance structure to reduce code duplication. The base class **GradientDescent** implements a fitting procedure consisting of a precomputation step, an optimization procedure over multiple iterations and a memory of the cost function values. The different optimization algorithms, i.e. vanilla gradient descent, momentum based gradient descent, Adagrad, RMSProp and Adam, are implemented as subclasses that override the

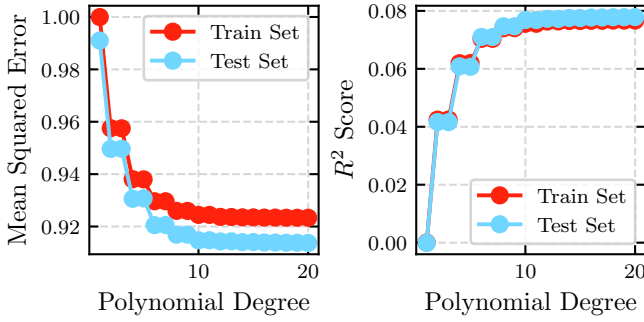


Figure 3 Mean squared error (MSE) and R^2 score for polynomial fits of different degrees to noisy data from the Runge function using ordinary least squares regression. $N_{\text{train}} = 80\,000$, $N_{\text{test}} = 20\,000$.

update rule for the parameters $\vec{\theta}$ in each iteration. The cost functions for OLS, Ridge and Lasso regression are also implemented as separate classes that provide methods to calculate the cost and its gradient. The stochastic gradient descent methods are implemented as further subclasses that modify the data used for fitting in each iteration. In the stochastic gradient descent method, the cost history property is furthermore modified to return the per epoch average of the cost function values. The resampling methods, i.e. bootstrapping and k-fold cross-validation, are implemented as methods with identical interfaces which provide multiple sets of training and test data. This allows to easily switch between the different resampling methods when evaluating the performance of a model.

III. RESULTS AND DISCUSSION

A. Influence of the Number of Parameters on Model Performance

1. Ordinary Least Squares

Even the best optimization algorithm can not turn a bad model into a good one. If a model is not suited to describe the trend in the data irrelevant of the parameters, it is logical to assume that no optimization algorithm can find a good fit. A common approach to counteract this problem is to increase the number of parameters in a model and use a very flexible model, e.g. a polynomial of high degree. In this section the influence of the number of parameters on the model performance is studied in the context of ordinary least squares (OLS) regression.

How the mean squared error (MSE) and the R^2 score depend on the polynomial degree of the model is shown in fig. 3. As expected, the MSE decreases and the R^2 score increases with increasing polynomial degree. However, it is also visible that for very high polynomial degrees the performance does no longer improve significantly. Using a dataset with 80 000 samples, no negative side effects of

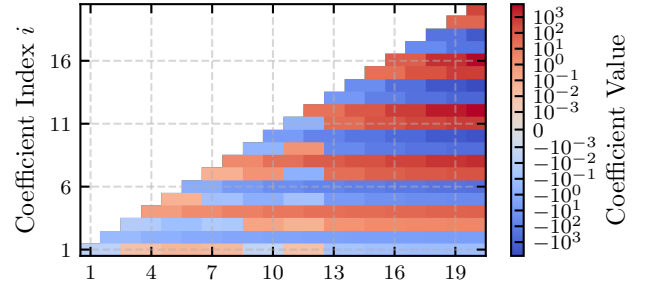


Figure 4 Parameter values for polynomial fits of different degrees to noisy data from the Runge function using ordinary least squares regression. $N_{\text{train}} = 80\,000$.

overfitting are visible even for polynomial degrees as high as 20. To highlight the danger of negative impact due to high parameter count it is also interesting to study the parameter values of the fitted models. Figure 4 shows the parameter values for polynomial fits of different degrees to the same dataset. It is visible that for high polynomial degrees the parameter values become very large, reaching values of up to $\pm 10^4$. Especially it is observable that the parameter values flip sign for every second parameter, i.e. compensating negative effects of one parameter with the next. While such behavior is not necessarily a problem within the feature space of the training data, it can lead to bad performance outside of this feature space, i.e. performance that is worse than the most simple approximation of constant output values. This is especially relevant for extrapolation tasks, where the model is used to predict values outside of the feature space of the training data. In such cases, the model can produce completely meaningless results.

In the limit of small datasets this issue becomes even more relevant. As the number of parameters approaches the number of data points, the model can fit the data perfectly, leading to an MSE of zero. However, this is usually not a desirable outcome, as the model will not generalize well to new data, as it has simply “memorized” the noise in the training data. This is a classic example of overfitting, where the model performs well on the training data but poorly on unseen data. In such cases, it is crucial to use techniques to prevent overfitting, such as regularization or cross-validation.

2. Regularization Techniques

To counteract the negative effects of high parameter count, regularization techniques such as Ridge and Lasso regression can be used. These techniques add a penalty term to the cost function that discourages large parameter values. In Ridge regression, the penalty term is proportional to the square of the parameter values, while in Lasso regression, it is proportional to the absolute value of the parameter values. This leads to a trade-off be-

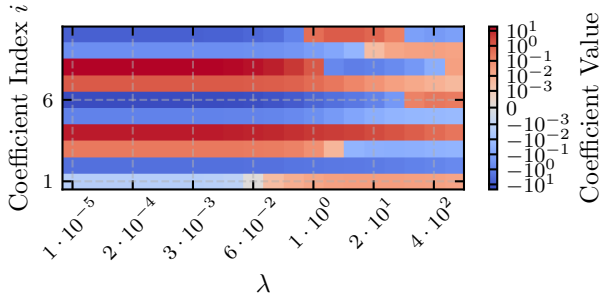


Figure 5 Parameter values for polynomial fits of different degrees to noisy data from the Runge function using Ridge regression with different regularization strengths λ . $N_{\text{train}} = 80\,000$.

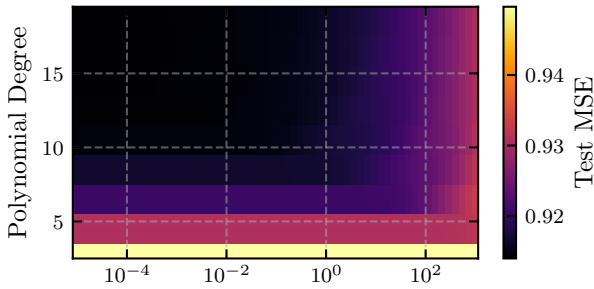


Figure 6 Mean squared error (MSE) for polynomial fits of different degrees to noisy data from the Runge function using Ridge regression with different regularization strengths λ . $N_{\text{train}} = 80\,000$, $N_{\text{test}} = 20\,000$.

tween fitting the data well and keeping the parameter values small. With an increasing regularization strength λ the parameter values are pushed towards zero, as visible in fig. 5. This effect is especially strong for $\lambda > 0$. For very high regularization strengths the parameter values become very small, leading to a model that is almost constant. This is also visible in fig. 6, where the MSE is shown for polynomial fits of different degrees to noisy data from the Runge function using Ridge regression with different regularization strengths λ . For very high regularization strengths the MSE increases significantly, as the model is not flexible enough to fit the data well. The optimal regularization strength is promoted to a hyperparameter that needs to be tuned to the problem at hand. However, with a suitable choice of λ it is possible to use models with a high number of parameters without suffering from the negative effects of overfitting.

B. Stochastic Gradient Descent

Figure 7 shows the large decrease in computational cost, i.e. the decrease in computation time for 1000 epochs when using SGD instead of GD. The computation time decreases from 14.82 s in the case of OLS to

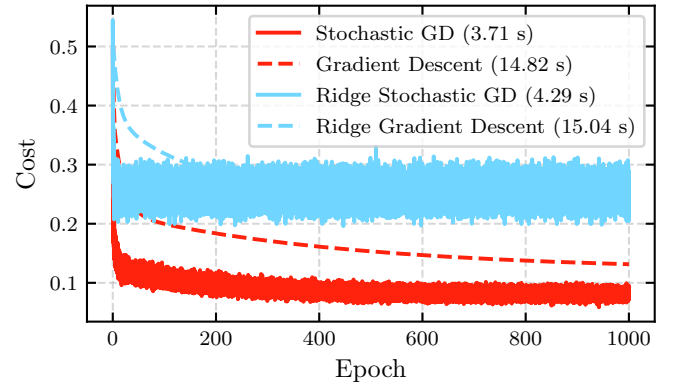


Figure 7 Convergence of GD and SGD for polynomial fits of degree 10 to noisy data from the Runge function using OLS and Ridge regression with $\lambda = 0.1$. $N_{\text{train}} = 800\,000$, $B = 512$, $N_{\text{batches}} = 100$ and $\sigma = 0.1$.

3.71 s. This is a decrease by over a factor of 3. For Ridge regression the computation time decreases from 15.04 s to 4.29 s. It is furthermore visible that the convergence of SGD is significantly faster during the first epochs as the parameters are updated more frequently. This leads to a significant decrease in the cost function during the first epochs, as the parameters are updated more frequently.

However, a second aspect of SGD is visible in fig. 7. While GD converges smoothly to the optimal solution, SGD shows significant oscillations around the optimal solution. This is a direct consequence of the increased variance in the gradient estimate, as the gradient is only computed over a small subset of the data. This can lead to slower convergence and even no convergence at all, if the batch size is too small or the noise in the data is too high. The intrinsic noise in the gradient estimate leads also to the issue, that SGD may be unable to reach an optimal solution with a large amount of noise in the training data. To counteract this problem, the noise in the dataset has been reduced by one order of magnitude compared to the previous sections. However, even with a reduced noise level, SGD is unable to reach the optimal solution. Further, fine-tuning of the new hyperparameters introduced by SGD, i.e. the batch size and the batches per epoch, could lead to better results. However, this is a non-trivial task and is highly dependent on the problem at hand. To arrive at a robust solution it might be necessary to increase the batch size until reaching the limit of full-batch GD, which would defeat the purpose of using SGD in the first place.

C. Effect of Learning Rate on Convergence

A crucial hyperparameter in gradient-based optimization algorithms is the learning rate η . The learning rate determines the step size in the direction of the negative gradient and thus has a significant impact on the convergence behavior of the optimization algorithm. A learning

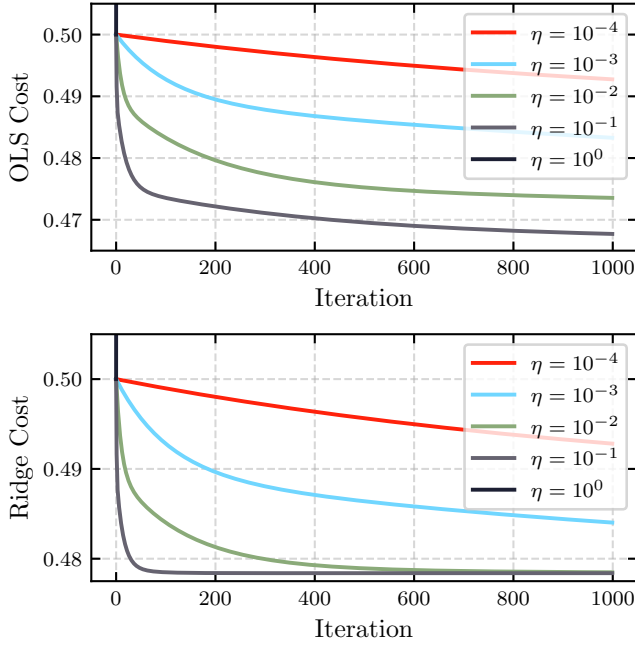


Figure 8 Convergence of GD for polynomial fits of degree 10 to noisy data from the Runge function using OLS and Ridge regression with $\lambda = 0.1$. $N_{\text{train}} = 80000$, $N_{\text{iterations}} = 1000$ with different learning rates η .

rate that is too high can lead to divergence, as the optimization algorithm overshoots the optimal solution. On the other hand, a learning rate that is too low can lead to very slow convergence, as the optimization algorithm takes very small steps towards the optimal solution. In this section the effect of the learning rate on the convergence behavior of GD is studied.

In fig. 8 it is easily observable, that the convergence towards the minimum of the cost function accelerates with increasing learning rate. However, it is also visible that for very high learning rates, i.e. $\eta \geq 1$, the optimization algorithm diverges, as the cost function increases instead of decreasing. This is a direct consequence of the optimization algorithm overshooting the optimal solution and thus moving away from it instead of towards it. For very low learning rates, i.e. $\eta \leq 0.001$, the convergence is very slow, as the optimization algorithm takes very small steps towards the optimal solution. In such cases, it can be beneficial to increase the learning rate to speed up convergence. However, this comes at the risk of divergence, if the learning rate is increased too much. Thus, it is crucial to find a suitable learning rate that balances convergence speed and stability.

D. Alternative Optimization Algorithms

A different approach to limit the computational cost of fitting models with a high number of parameters is to use alternative optimization algorithms that reduce the number of gradient evaluations before reaching convergence.

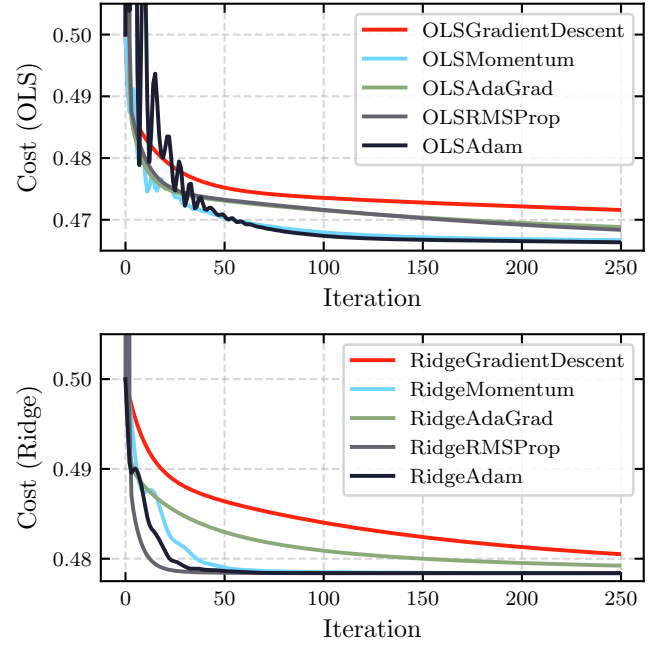


Figure 9 Minimization of OLS and Ridge regression cost functions using GD, Momentum GD, Adagrad, RMSProp and Adam optimization algorithms. $N_{\text{train}} = 80000$, $N_{\text{iterations}} = 250$, $p = 10$ and learning rates $\eta_{\text{OLS}} = 0.1$, $\eta_{\text{Ridge}} = 0.01$.

The optimized algorithms as introduced in Section II.A.2 are evaluated with regard to their convergence behavior on the same dataset and model.

Figure 9 shows the convergence behavior of GD, Momentum GD, Adagrad, RMSProp and Adam optimization algorithms for OLS and Ridge regression. It is visible that all optimized algorithms converge faster than GD, with Adam showing the best performance. While GD is unable to reach perfect convergence within 250 iterations. Especially for the Ridge regression cost function, the optimized algorithms converge within a very short frame. On the contrary it is also visible that in multiple optimized algorithms there are stark oscillations in the convergence behavior. This is especially visible for the Momentum GD algorithm and the Adam algorithm. While these oscillations can be reduced by fine-tuning the hyperparameters of the algorithms, they are an intrinsic property of the algorithms and cannot be completely eliminated. However, as the overall convergence behavior is significantly improved compared to GD, these oscillations are usually not a problem in practice.

E. Bias-Variance Tradeoff and Resampling Techniques

To evaluate the bias-variance tradeoff of the optimized models, the MSE is decomposed into its bias and variance components as introduced in section II.A.1. The results are shown in fig. 10. To accurately depict the bias-variance tradeoff, there were two sets of test data used. To compute the bias, no noise was added to the

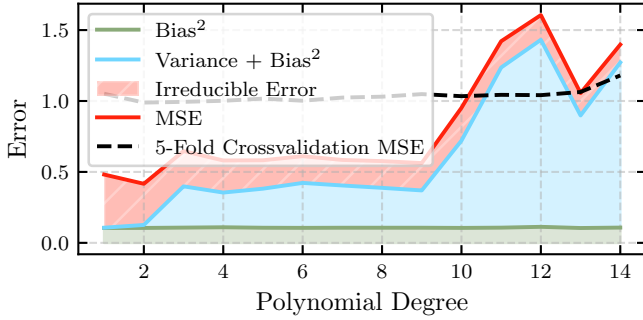


Figure 10 Bias-variance decomposition of the mean squared error (MSE) for polynomial fits of different degrees to noisy data from the Runge function using OLS. The Bias-Variance decomposition is calculated from bootstrapped samples. The MSE is also calculated using 5-fold cross-validation and bootstrap resampling techniques. $N_{\text{train}} = 80, N_{\text{test}} = 20$.

test data, while for the rest of the computations the same noise level as in the training data was used. It is visible that for increasing polynomial degrees the variance increases, while the bias stays almost constant. This is a direct consequence of the increased flexibility of the model with increasing polynomial degree. To ensure numerical stability, Ridge regression with a very small regularization strength of $\lambda = 1 \times 10^{-10}$ has been used to compute the bias-variance decomposition in an approximation of OLS. This ensures that the matrix inversion in the computation of the model parameters is numerically stable, while the regularization term has almost no effect on the model performance. The optimal model complexity is usually found at the point where the sum of bias and variance is minimal. Usually this coincides with the point of the minimum of the mean squared error. How the MSE behaves on average for k -fold cross-validation and bootstrap resampling techniques is also shown in fig. 10. Both resampling techniques display a minimum in the MSE for the polynomial degree of 2. The crossvalidation technique presents a much more constant MSE value over the entire range of polynomial degrees, while the bootstrap technique expresses a more pronounced minimum. This indicates that the bootstrap technique is more sensitive to the choice of polynomial degree and thus provides a better estimate in the case of hyperparameter tuning at the cost of a much higher computational cost.

This trend of optimal model complexity being achieved somewhere between the high bias case of low parameter count and the high variance case of high parameter count is a general property of machine learning models and is not limited to polynomial regression with OLS cost functions. As seen in fig. 11 this trend of a minimum in the MSE is also observable for Ridge and Lasso regression.

It is also observable, that the minimum of the MSE is shifted towards higher polynomial degrees for Ridge and Lasso regression with a slower increase in the mean squared error above the optimal polynomial degree compared to OLS regression. This is a direct consequence

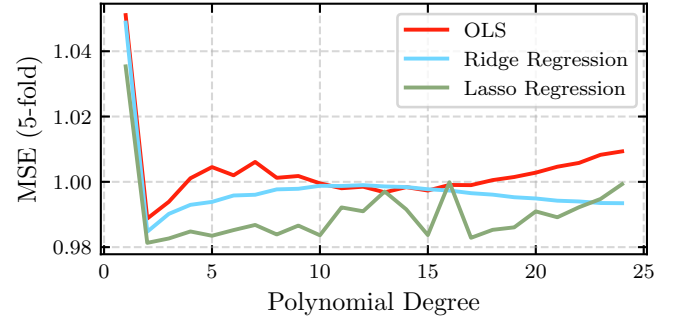


Figure 11 Mean squared error (MSE) for polynomial fits of different degrees to noisy data from the Runge function using OLS, Ridge and Lasso regression cost functions with 5-fold cross-validation resampling technique. $N_{\text{train}} = 240, N_{\text{test}} = 60$ and $\lambda = 0.1$ for Ridge and Lasso regression.

of the regularization term in the cost function, which decreases the effective degrees of freedom of the model. Thus, a model with a higher number of parameters is needed to achieve the same flexibility as a model with a lower number of parameters without regularization. This effect is especially strong for Lasso regression, where the regularization term can lead to some parameters being set to zero, effectively removing them from the model. This leads to a significant reduction in the effective degrees of freedom of the model and thus a shift of the optimal polynomial degree towards higher values. The reduction in effective degrees of freedom always depends on the data at hand and the chosen regularization strength λ and thus cannot be quantified in a general way.

IV. CONCLUSION

It was shown that in the context of big data and complex models to describe relations in the data there are many challenges to overcome. The choice of model, on what metric to optimize the model – i.e. the cost function – and how to perform the optimization are all crucial choices that can have a significant impact on the performance of the model. The use of regularization techniques can help to prevent overfitting and improve the generalization performance of the model. The number of degrees of freedom in the model directly influences the bias-variance trade-off and only with a good balance between the two can a model perform well on unseen data. Finally, the choice of optimization algorithm can have a significant impact on the computational cost of the models training process. Using good optimization algorithms can help to speed up the convergence of the models parameters. Combining this with other innovative techniques such as stochastic gradient descent can help to further reduce the computational cost of training complex models on large datasets.

V. PERSPECTIVE

With the increasing availability of large datasets and the growing complexity of models, there is an increasing need for efficient optimization techniques that can handle the computational challenges associated with big data. Especially in the context of deep learning, where models can have millions of parameters and require large amounts of data to train, the choice of optimization algorithm can have a significant impact on the performance of the model. As to limit the computational footprint of such data-driven methods, the search for more efficient optimization techniques is an ongoing field of research. There will also be further advances in the methods to choose hyperparameters of model training to make the usage of numerical models easier and more efficient to use.

As the scope of this paper was limited to the study of a simple toy dataset with simple models, the results cannot be directly transferred to more complex models and datasets, and need to be researched accordingly. However, the general trends observed in this study can be expected to hold true for more complex models and datasets as well. The choice of optimization algorithm and cost function can have a significant impact on the performance of the model, and reducing the computational cost of training is an important consideration in the context of big data.

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