Advanced Methods for Bayesian Optimization in Complex Scenarios Course

Presented by: Eduardo C. Garrido-Merchán.

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- Introduction and Motivation.
- Fundamentals of Bayesian Optimization.

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- References.

First Session: Bayesian optimization fundamentals

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Introduction.

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Companies face complex scenarios dealing with lots of scenarios!



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- Prone to human bias.

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- It may be possible to test various models in parallel.

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Optimization is a challenging task in real-life choices!

Example: Deep Neural Network for object recognition.





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Parameters to tune: Number of neurons, number of layers, learning-rate, level of regularization, momentum, etc.

Example: Deep Neural Network for object recognition.



Parameters to tune: Number of neurons, number of layers, learning-rate, level of regularization, momentum, etc. If **multiple processors** were available, we could test **various configurations in parallel**, in order to **gain more information**.

Example: new **plastic solar cells** for transforming light into electricity.







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Explore **millions of candidate molecule structures** to identify the compounds with the best properties.

Example: control system for a robot that is able to grasp objects.



Finger Joint Trajectories



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Example: control system for a robot that is able to grasp objects.



Finger Joint Trajectories



Parameters to tune: initial pose for the robot's hand and finger joint trajectories.

Very expensive evaluations.



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 Very expensive evaluations.



 The objective is a black-box.

 Very expensive evaluations.

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 The objective is a black-box.

 The evaluation can be noisy.

► Very expensive evaluations.

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The evaluation can be noisy.

Evaluations may be done in parallel.

Bayesian optimization methods can be used to solve these problems!











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- 1. Get initial sample.
- 2. Fit a model to the data: $p(y|x, \mathcal{D}_n)$.
- 3. Select data collection strategy: $\alpha(x) = \mathsf{E}_{p(y|x,\mathcal{D}_n)}[U(y|x,\mathcal{D}_n)]$
- 4. Optimize acquisition function $\alpha(x)$.
- 5. Collect data and update model.
- 6. Repeat! _____

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$$h_j(\mathbf{x}) = \tanh\left(\sum_{i=1}^I x_i w_{ji}\right)$$

$$f(\mathbf{x}) = \sum_{j=1}^{H} v_j h_j(\mathbf{x})$$

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Posterior Dist.

Predictive Dist.

 $p(\mathbf{W}|\text{Data}) = p(\mathbf{W})p(\text{Data}|\mathbf{W})/p(\text{Data})$ $p(y|\text{Data}, x) = \int p(y|\mathbf{W}, x)p(\mathbf{W}|\text{Data})d\mathbf{W}$



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Challenges: The model should be non-parametric (the world is complicated) and computing p(Data) is intractable!



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Challenges: The model should be non-parametric (the world is complicated) and computing p(Data) is intractable!

Solved by setting $p(W) = \prod_{ij} \mathcal{N}(w_{ji}|0, \sigma^2 H^{-1})$ and letting $H \to \infty!$

Bayesian Optimization vs. Uniform Exploration



Tuning LDA on a collection of Wikepida articles (Snoek et al., 2012).

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Where to evaluate **next**?



Where to evaluate next?



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Where to evaluate next?



Exploration: seek places with high variance.

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- **Exploration:** seek places with high variance.
- **Exploitation:** seek places with low mean.

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$$\alpha(\mathsf{x}) = \mathbb{E}_{p(y^{\star}|\mathcal{D}_N,\mathsf{x})} \left[U(y^{\star}|\mathsf{x},\mathcal{D}_N) \right]$$

Some Acquisition Functions Let $\nu = \min\{y_1, \dots, y_N\}$ and $\gamma(x) = \frac{\nu - \mu(x)}{\sigma(x)}$.

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Probability of Improvement:

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Lower Confidence Bound:

$$\alpha(\mathbf{x}) = -(\mu(\mathbf{x}) - \kappa\sigma(\mathbf{x}))$$

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Entropy Search:

$$U(y^*|\mathcal{D}_N, \mathbf{x}) = \mathsf{H}[p(\mathbf{x}_{\min}|\mathcal{D}_N)] - \mathsf{H}[p(\mathbf{x}_{\min}|\mathcal{D}_N \cup \{\mathbf{x}, y^*\})]$$

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Some Acquisition Functions: Prob. Improvement



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Some Acquisition Functions: Exp. Improvement



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Some Acquisition Functions: Lower Conf. Bound



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Some Acquisition Functions: Entropy Search



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The minimizer, x*, can be modelled as a random variable!

Information is measured by the **entropy** of $p(x^*|D)$.

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The acquisition function is

$$\alpha(\mathbf{x}) = \mathsf{H}[\mathbf{x}^* | \mathcal{D}_t] - \mathbb{E}_{\mathbf{y}} \Big[\mathsf{H}[\mathbf{x}^* | \mathcal{D}_t \cup \{\mathbf{x}, \mathbf{y}\}] \Big| \mathcal{D}_t, \mathbf{x} \Big]$$
(1)

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(1)
How much we know about \mathbf{x}^* now.

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Structured SVM for protein motif finding (Snoek et al., 2012).

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Slice sampling means no additional hyper-parameters!

(Neal, 2003)

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(Neal, 2003)

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GP fitting an unknown function using Maximum Likelihood



GP fitting an unknown function sampling hyperparameters



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$$\hat{\alpha}(\mathsf{x}) = \int \alpha(\mathsf{x};\theta) p(\theta|\mathsf{y}) d\theta \approx \frac{1}{K} \sum_{k=1}^{K} \alpha(\mathsf{x};\theta^{(k)}) \quad \theta^{(k)} \sim p(\theta|\mathsf{y}),$$

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(Snoek et al., 2012)

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Length-scale specific expected improvement

(Snoek et al., 2012)

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(Snoek et al., 2012)

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MCMC estimation vs. Maximization



Logistic regression on the MNIST (Snoek et al., 2012).

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- Different inputs may have different computational costs, e.g., training a neural network of increasing hidden layers and units.
- Better to do cheap evaluations before expensive ones!
- The evaluation costs are unknown but they can be recorded and then modeled with an additional Gaussian process.

Expected Improvement per-second:

$$\alpha(\mathsf{x}) = \frac{\sigma(\mathsf{x}) \left(\gamma(\mathsf{x}) \Phi\left(\gamma(\mathsf{x})\right) + \phi(\gamma(\mathsf{x}))\right)}{\exp\left\{\mu_{\mathsf{log-time}}(\mathsf{x})\right\}}$$

(Snoek et al., 2012)



















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Deep neural network on the CIFAR dataset (Snoek et al., 2012)

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Gaussian processes are not the only probabilistic surrogate model!

1. **Computationally expensive**: GPs scale poorly due to cubic observation complexity.
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- 5. **Bayesian neural networks**: Able to model complex patterns and scalable.
- 6. **Deep Gaussian Process**: Increased expressivity, advantages of GPs.

Ensemble method where the predictors are random regression trees trained on random subsamples of the data.

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 Trees are grown on different bootstrap samples of the data.

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- This guarantees that each tree is slightly different.

Very cheap to compute and massively paralelizable!

Random Forest: Predictive Distribution



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Random Forest: Predictive Distribution



$$p(f^{\star}|\mathcal{D}_n) = \mathcal{N}(f^{\star}|\overline{\mu},\overline{\nu}^2)$$

(Hutter et al., 2011)

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(Shahriari et al., 2016)



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- Allows for a lot of evaluations (good when the objective is cheap).
- Too confident intervals in far away from the data regions.
- Conflictive predictions can cause the variance to be too high.
- Discontinuous: Difficult to optimize the acquisition function.
- No parameters to tune.



Neural networks scale well to the training data (linear cost).

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Trained very fast on GPUs.



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They are an alternative to GPs to allow for a large number observations!

The posterior distribution of the networks weights ${\sf W}$ is intractable!

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Several techniques considered to approximate the predictive distribution:

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- ▶ Point estimates and Bayesian linear-models in the last layer.

Trade-off between accuracy of the predictive distribution and scalability! Still a lot of research going on!

Many of the methods described are implemented into **BOTorch** using Python. https://botorch.org/



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1. **Modularity**: Plugin new models, acquisition functions and optimizers.

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Software for Bayesian Optimization

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Other tools: SMAC3 (Python-RFs), GPyOpt (Python3), Spearmint (Python2.7-sampling), mlrMBO (R).

Time to practice!

- 1. Bayesian optimization of a benchmark optimization function.
- 2. Bayesian optimization of the hyper-parameters of a machine learning model.
- 3. Bayesian optimization of the hyper-paramaters of a deep reinforcement learning algorithm.



Second Session: Advanced Bayesian optimization.

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(Parallel) Multi-objective Bayesian optimization with constraints.

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Optimal design of **hardware accelerator** for neural network predictions.





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Optimal design of **hardware accelerator** for neural network predictions.





Goals:

- Minimize prediction error.
- Minimize prediction time.

Optimal design of **hardware accelerator** for neural network predictions.





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Constrained to:

- Chip area below a value.
- Power consumption below a level.

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Goals:

time.

 Minimize prediction error.

Minimize **prediction**

Constrained to:

- **Chip area** below a value.
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Challenges:

- **Complicated** constraints.
- Conflictive objectives.

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Pareto Set (Input space)





Pareto Set (Input space)



Pareto Frontier (value space)



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0.0 0.2 0.4 0.6 0.8

 x_1



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Pareto Set (Input space)



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 Outries

Pareto Frontier (value space)



Pareto Frontier (value space)

Pareto Set (Input space)





Additional challenges when dealing with several black-boxes.

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Simple approach: evaluate all the objectives and constraints at the same input location. Expected to be sub-optimal.

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Coupled evaluations

$$\overbrace{\textbf{K}_{t}}^{\text{Black-box } 1} \rightarrow Y_{t}^{1}$$

$$\overbrace{\text{Black-box } 2}^{\text{Black-box } 1} \rightarrow Y_{t}^{1}$$



Additional challenges when dealing with several black-boxes.

- Simple approach: evaluate all the objectives and constraints at the same input location. Expected to be sub-optimal.
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The Pareto set \mathcal{X}^* in the feasible space is a random variable!

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Information is measured by the **entropy** of $p(\mathcal{X}^*|\mathcal{D}_N)$.

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Optimized Samples Drawn from the Posterior





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The acquisition function is

$$\alpha(\mathbf{x}) = \mathsf{H}\big[\mathbf{x}^* \big| \mathcal{D}_t\big] - \mathbb{E}_{\mathbf{y}}\big[\mathsf{H}\big[\mathbf{x}^* \big| \mathcal{D}_t \cup \{\mathbf{x}, \mathbf{y}\}\big] \Big| \mathcal{D}_t, \mathbf{x}\big] \quad (1)$$

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$$\alpha \left(\mathbf{x} \right) = \mathbf{H} \left[\mathbf{x}^* | \mathcal{D}_t \right] - \mathbb{E}_{\mathbf{y}} \left[\mathbf{H} \left[\mathbf{x}^* | \mathcal{D}_t \cup \{ \mathbf{x}, \mathbf{y} \} \right] \Big| \mathcal{D}_t, \mathbf{x} \right]$$
(1)
How much we know about \mathbf{x}^* now.

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The acquisition function is


Information-based Approach

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$$\mathsf{H}[\mathcal{X}^{\star}|\mathcal{D}_{t}] - \mathbb{E}_{\mathbf{y}}\Big[\mathsf{H}\big[\mathcal{X}^{\star}|\mathcal{D}_{t} \cup \{\mathbf{x},\mathbf{y}\}\big]\Big|\mathcal{D}_{t},\mathbf{x}\Big] \equiv \mathsf{MI}(\mathbf{y},\mathcal{X}^{\star}) \quad \text{(ESMOC)}$$

$$\begin{aligned} &\mathsf{H}[\mathcal{X}^{\star}|\mathcal{D}_{t}] - \mathbb{E}_{\mathbf{y}}\Big[\mathsf{H}\big[\mathcal{X}^{\star}|\mathcal{D}_{t}\cup\{\mathbf{x},\mathbf{y}\}\big]\Big|\mathcal{D}_{t},\mathbf{x}\Big] \equiv \mathsf{MI}(\mathbf{y},\mathcal{X}^{\star}) \quad (\mathsf{ESMOC}) \\ &\mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x}] - \mathbb{E}_{\mathcal{X}^{\star}}\Big[\mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x},\mathcal{X}^{\star}]\Big|\mathcal{D}_{t},\mathbf{x}\Big] \equiv \mathsf{MI}(\mathcal{X}^{\star},\mathbf{y}) \quad (\mathsf{PESMOC}) \end{aligned}$$

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Gaussian distribution

$$\begin{aligned} \mathsf{H}[\mathcal{X}^{\star}|\mathcal{D}_{t}] - \mathbb{E}_{\mathbf{y}} \Big[\mathsf{H}[\mathcal{X}^{\star}|\mathcal{D}_{t} \cup \{\mathbf{x},\mathbf{y}\}] \Big| \mathcal{D}_{t},\mathbf{x} \Big] &\equiv \mathsf{MI}(\mathbf{y},\mathcal{X}^{\star}) \quad (\mathsf{ESMOC}) \\ & \mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x}] - \mathbb{E}_{\mathcal{X}^{\star}}^{\star} \Big[\mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x},\mathcal{X}^{\star}] \Big| \mathcal{D}_{t},\mathbf{x} \Big] &\equiv \mathsf{MI}(\mathcal{X}^{\star},\mathbf{y}) \quad (\mathsf{PESMOC}) \\ & \mathsf{Gaussian} \\ & \mathsf{distribution} \end{aligned}$$

We swap y and \mathcal{X}^{\star} to obtain a reformulation of the acquisition function.

$$\begin{array}{c} \mathsf{H}[\mathcal{X}^{\star}|\mathcal{D}_{t}] - \mathbb{E}_{\mathbf{y}} \Big[\mathsf{H}[\mathcal{X}^{\star}|\mathcal{D}_{t} \cup \{\mathbf{x},\mathbf{y}\}] \Big| \mathcal{D}_{t},\mathbf{x} \Big] \equiv \mathsf{MI}(\mathbf{y},\mathcal{X}^{\star}) \quad (\mathsf{ESMOC}) \\ \\ \mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x}] - \mathbb{E}_{\mathcal{X}^{\star}}^{\star} \Big[\mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x},\mathcal{X}^{\star}] \Big| \mathcal{D}_{t},\mathbf{x} \Big] \equiv \mathsf{MI}(\mathcal{X}^{\star},\mathbf{y}) \quad (\mathsf{PESMOC}) \\ \\ \hline \\ \mathbf{Gaussian} \\ \mathbf{distribution} \quad \begin{array}{c} \mathsf{Approximated by} \\ \mathsf{sampling from } p(\mathcal{X}^{\star}|\mathcal{D}_{t}) \end{array} \right]$$

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We swap y and \mathcal{X}^{\star} to obtain a reformulation of the acquisition function.

$$\begin{array}{c} \mathsf{H}[\mathcal{X}^{\star}|\mathcal{D}_{t}] - \mathbb{E}_{\mathbf{y}} \Big[\mathsf{H}[\mathcal{X}^{\star}|\mathcal{D}_{t} \cup \{\mathbf{x},\mathbf{y}\}] \Big| \mathcal{D}_{t},\mathbf{x} \Big] \equiv \mathsf{MI}(\mathcal{Y},\mathcal{X}^{\star}) \quad (\mathsf{ESMOC}) \\ \\ \mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x}] - \mathbb{E}_{\mathcal{X}^{\star}}^{\star} \Big[\mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x},\mathcal{X}^{\star}] \Big| \mathcal{D}_{t},\mathbf{x} \Big] \equiv \mathsf{MI}(\mathcal{X}^{\star},\mathbf{y}) \quad (\mathsf{PESMOC}) \\ \\ \hline \\ \mathbf{Gaussian} \\ \mathbf{distribution} \quad \mathbf{Approximated by} \\ \mathbf{sampling from } p(\mathcal{X}^{\star}|\mathcal{D}_{t}) \\ \hline \\ \mathbf{K}^{\star} \text{ dominates any other point in } \mathcal{X} \\ \end{array} \right].$$

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$$\begin{aligned} & \mathsf{H}[\mathcal{X}^{*}|\mathcal{D}_{t}] - \mathbb{E}_{\mathbf{y}} \Big[\mathsf{H}[\mathcal{X}^{*}|\mathcal{D}_{t} \cup \{\mathbf{x},\mathbf{y}\}] \Big| \mathcal{D}_{t},\mathbf{x} \Big] \equiv \mathsf{MI}(\mathbf{y},\mathcal{X}^{*}) \quad (\mathsf{ESMOC}) \\ & \mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x}] - \mathbb{E}_{\mathcal{X}^{*}} \Big[\mathsf{H}[\mathbf{y}|\mathcal{D}_{t},\mathbf{x},\mathcal{X}^{*}] \Big| \mathcal{D}_{t},\mathbf{x} \Big] \equiv \mathsf{MI}(\mathcal{X}^{*},\mathbf{y}) \quad (\mathsf{PESMOC}) \\ & \mathsf{Gaussian} \\ & \mathsf{distribution} \quad \mathsf{Approximated by} \\ & \mathsf{sampling from } p(\mathcal{X}^{*}|\mathcal{D}_{t}) \\ & \mathsf{Factorized Gaussian approximation} \\ & \mathsf{with expectation} \\ & \mathsf{One acquisition} \\ & \mathsf{per black-box} \\ & \mathsf{A}(\mathbf{x}) \approx \sum_{c=1}^{C} \log v_{c}^{PD}(\mathbf{x}) - \frac{1}{M} \sum_{m=1}^{M} \left(\sum_{c=1}^{C} \log v_{c}^{CPD}(\mathbf{x}|\mathcal{X}_{(m)}) \right) + \\ & \sum_{k=1}^{K} \log v_{k}^{PD}(\mathbf{x}) - \frac{1}{M} \sum_{m=1}^{M} \left(\sum_{k=1}^{K} \log v_{k}^{CPD}(\mathbf{x}|\mathcal{X}_{(m)}^{*}) \right) = \sum_{i=1}^{C+K} \alpha_{i}(\mathbf{x}) \end{aligned}$$

Example of PES' acquisition



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Example of PES' acquisition $v_1^{PD}(x)$







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Finding a Fast and Accurate Neural Network Average Pareto Front 100 Function Evaluations



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Finding a Fast and Accurate Neural Network Average Pareto Front 100 Function Evaluations



(Hernández-Lobato et al., 2016)

Finding a Fast and Accurate Neural Network Average Pareto Front 100 Function Evaluations



(Hernández-Lobato et al., 2016)

Low energy hardware accelerator



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Low energy hardware accelerator



(Hernández-Lobato et al., 2016)

Traditional Bayesian optimization is sequential!

Traditional Bayesian optimization is sequential!



Traditional Bayesian optimization is sequential!



Computing clusters let us do many things at once!

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Parallel experiments should be highly informative but different!

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Parallel Predictive Entropy Search

Choose a set Q points $S_t = \{x_q\}_{q=1}^Q$ to minimize the entropy of x^* .

 $\mathsf{H}\big[\mathbf{x}^{\star}\big|\mathcal{D}_{t}\big] - \mathbb{E}_{\mathbf{y}}\Big[\mathsf{H}\big[\mathbf{x}^{\star}\big|\mathcal{D}_{t} \cup \{\mathbf{x}_{q}, y_{q}\}_{q=1}^{Q}\big] \Big|\mathcal{D}_{t}, \mathbf{x}\Big] \equiv \mathsf{MI}(\mathbf{y}, \mathbf{x}^{\star}) \quad \text{(Parallel ES)}$

(Shah and Ghahramani, 2015)

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(Shah and Ghahramani, 2015)

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$$\begin{array}{c} \mathsf{Multi-variate} \\ \mathsf{Gaussian} \\ \mathsf{distribution} \end{array}$$

(Shah and Ghahramani, 2015)

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$$\begin{aligned} \mathsf{Multi-variate}_{\mathsf{Gaussian}} \text{ ampling from } p(\mathbf{x}^{\star}|\mathcal{D}_{t}) \text{ Multivariate Gaussian approximation}_{\mathbf{x}^{\star} \text{ is better than any other point in } \mathcal{X}} \end{aligned}$$

$$\begin{aligned} \alpha(\mathbf{X}) &= \log |\mathbf{V}^{\mathrm{PD}}(\mathbf{X})| - \frac{1}{M} \sum_{m=1}^{M} \log |\mathbf{V}^{\mathrm{CPD}}(\mathbf{X}|\mathbf{x}_{(m)}^{\star})| \end{aligned}$$

(Shah and Ghahramani, 2015)

Choose a set Q points $S_t = \{x_q\}_{q=1}^Q$ to minimize the entropy of x^* .

It is possible to compute the gradient of $\alpha(\cdot)$ w.r.t. each $x_q \in \mathcal{S}_t!$

(Shah and Ghahramani, 2015)

Parallel Predictive Entropy Search: Level Curves



(Shah and Ghahramani, 2015)

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Parallel Predictive Entropy Search: Results



(Shah and Ghahramani, 2015)

Standard GPs assume continuous input variables which makes BO with integer-valued or categorical challenging.

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A naive approach is to round the suggested value to the closest integer or to the closest one-hot encoding.

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Standard GPs assume continuous input variables which makes BO with integer-valued or categorical challenging.

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The BO algorithm may get stuck and may always perform the next evaluation at the same input location!

Rounding inside of the wrapper works but makes the objective flat!



Rounding inside of the wrapper works but makes the objective flat!



A modified GP covariance function accounts for this:

$$C_{\text{new}}(\mathsf{x}_n,\mathsf{x}_{n'})=C(T(\mathsf{x}_n),T(\mathsf{x}_{n'});\boldsymbol{\theta})$$

where $T(\cdot)$ does the rounding to the closest integer or one-hot encoding.

Rounding inside of the wrapper works but makes the objective flat!



A modified GP covariance function accounts for this:

$$C_{\text{new}}(\mathsf{x}_n,\mathsf{x}_{n'})=C(T(\mathsf{x}_n),T(\mathsf{x}_{n'});\boldsymbol{\theta})$$

where $T(\cdot)$ does the rounding to the closest integer or one-hot encoding.



The GP predictive distribution is constant across all variables that lead to the same integer or one-hot-encoding.

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Similar results for categorical variables!

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One continuous variable and two integer-valued variables.

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Common aspects of many machine learning algorithms:

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Can we use partial training information and a model to determine which hyper-parameter configuration is going to be optimal?

Yes, that is precisely what Freeze-Thaw BO does! (Swersky et al., 2014)

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A GP Kernel for Training Curves

We want to specify a kernel that supports exponentially decaying functions of the form $\exp\{-\lambda t\}$ for $t, \lambda \ge 0$.

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The covariance between inputs t and t' is:

$$C(t,t') = \int_0^\infty e^{-\lambda t} e^{-\lambda t'} \psi(\lambda;\alpha,\beta) d\lambda = \frac{\beta^\alpha}{(t+t'+\beta)^\alpha}$$

where $\psi(\lambda; \alpha, \beta)$ is a gamma distribution with parameters α and β .

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Inference on Asymptotic Values

A standard GP is used as the prior for the asymptotic values of each training curve.

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Hierarchical generative model:

$$p(\{\mathbf{y}_n\}_{n=1}^N | \{\mathbf{x}_n\}_{n=1}^N) = \int \left[\prod_{n=1}^N \mathcal{N}(\mathbf{y}_n | f_n \mathbf{1}, \mathbf{K}_{t_n})\right] \mathcal{N}(\mathbf{f} | \mathbf{m}, \mathbf{K}_{\mathbf{x}}) d\mathbf{f}$$

where

 $\begin{array}{ll} \mathsf{x}_n \equiv n \text{ configuration}, & \mathsf{y}_n \equiv n \text{ observed curve}, \\ f_n \equiv n \text{ asymptotic value}, & \mathsf{m} \equiv \mathsf{prior} \text{ asymptotic mean values}, \\ \mathsf{K}_{t_n} \equiv \mathsf{covariances} \text{ for curve values}, & \mathsf{K}_{\mathsf{x}} \equiv \mathsf{cov}. \text{ for asymptotic values} \end{array}$

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where

The joint distribution of $\{y\}_{n=1}^{N}$ and f is Gaussian and hence so it is the predictive distribution $p(f|\{y\}_{n=1}^{N})!$

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Inference on Asymptotic Values and BO



Inference on Asymptotic Values and BO



Bayesian Optimization:

•
$$p(f|\{y_n\}_{n=1}^N, \{x_n\}_{n=1}^N)$$
 determines asymptotic values.

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Inference on Asymptotic Values and BO



Bayesian Optimization:

- $p(f|\{y_n\}_{n=1}^N, \{x_n\}_{n=1}^N)$ determines asymptotic values.
- This distribution can be used to make intelligent decisions!
Inference on Asymptotic Values and BO



Bayesian Optimization:

- ▶ $p(f|\{y_n\}_{n=1}^N, \{x_n\}_{n=1}^N)$ determines asymptotic values.
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- Shall we train more one configuration or shall we start a new one?

Inference on Asymptotic Values and BO



Bayesian Optimization:

- ▶ $p(f|\{y_n\}_{n=1}^N, \{x_n\}_{n=1}^N)$ determines asymptotic values.
- This distribution can be used to make intelligent decisions!
- Shall we train more one configuration or shall we start a new one?
- A combination of EI and ES is used as the acquisition function.

(Swersky et al., 2014)

Freeze-Thaw BO in practice



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Freeze-Thaw BO in practice



(Swersky et al., 2014)

Multi-fidelity Bayesian optimization



- Concept of Fidelity: Fidelity refers to the accuracy or reliability of the information, we use different levels of accuracy.
- **Example:** # layers in NNs, # of timesteps for DRL.
- We assume that lower fidelities are correlated with higher.
- Cost-Efficiency: Leveraging computationally cheaper versions of the functions to guide the search process.
- The trick: The acquisition function should balance exploration at cheaper fidelities with exploitation at the highest fidelity level.

Multi-fidelity Bayesian optimization example

- Trace-aware knowledge-gradient acquisition function.
- It values observations of a point (x) and a set of fidelities (S) according to the ratio of the reduction in expected loss that it induces, to its computational cost.
- It measures the value of information per unit cost of sampling.
- It uses a function L() to measure the extent to which observing trace information improves the quality of the solution. L(0) will be the minimum.
- Its analytical expression basically penalizes the cost wrt the information obtained:

$$takg(x, \mathcal{S}) = rac{L(0) - L(x, \mathcal{S})}{cost(x, max(\mathcal{S}))}$$

High-dimensional Bayesian optimization



- GPs empirical performance tends to be lower if d > 7.
- The problem: The search space grows exponentially with the number of dimensions.
- The trick: We can project the high-dimensional problem into a lower-dimensional subspace that explains it well using embeddings.
- Find the hidden most explicative manifold for the data, then optimize there!
- Approaches differ in the type of embeddings (e.g. random), assumptions about the function (e.g. being a sum of functions), or use of models (Deep GP, GP-LVM.)

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High-dimensional Bayesian optimization example

- Sparse Axis-Aligned Subspace Bayesian Optimization (SAASBO)
- Goal: Identify sparse subspaces relevant to modeling the unknown objective function.
- Assumption: High function variability being captured by axis-aligned blocks of input features.
- Method: Use complex GP prior to consider a smaller class of functions.
- Effect: Turn most non-explicative dims off,
- Integration: Perform hyper-parameter sampling with NUTS and EI.

[kernel variance] [global shrinkage] [length scales] [function values] [observations]
$$\begin{split} & \sigma_k^2 \sim \mathcal{LN}(0, 10^2) \\ & \tau \sim \mathcal{HC}(\alpha) \\ & \rho_i \sim \mathcal{HC}(\tau) \\ & \mathbf{f} \sim \mathcal{N}(\mathbf{0}, K_{\mathbf{XX}}^{\psi}) \\ & \mathbf{y} \sim \mathcal{N}(\mathbf{f}, \sigma^2 \mathbb{1}_N) \end{split}$$

Bayesian optimization in a simplex (Portfolio optimization)



- Common financial metrics as Sharpe or Sortino ratio can be configured for a specific portfolio.
- ▶ For example using real-time ESG values of the assets.
- Garrido-Merchán, E. C., Piris, G. G., & Vaca, M. C. (2023). Bayesian optimization of ESG (Environmental Social Governance) financial investments. Environmental Research Communications, 5(5), 055003.

Conclusions and Further Work

- BO is a state-of-the-art class of methods used to optimize expensive and noisy black-box functions.
- We can generalize BO to tackle advanced scenarios: parallel constrained multi-obj, high-dim, multi-fidelity...
- BO can be applied in a wide array of applications: ML, DRL, finance, robotics, materials, business operations...
- Further work topics: causality, meta-BO, transfer learning, adaptation to specific domains.



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Thank you for your attention.

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