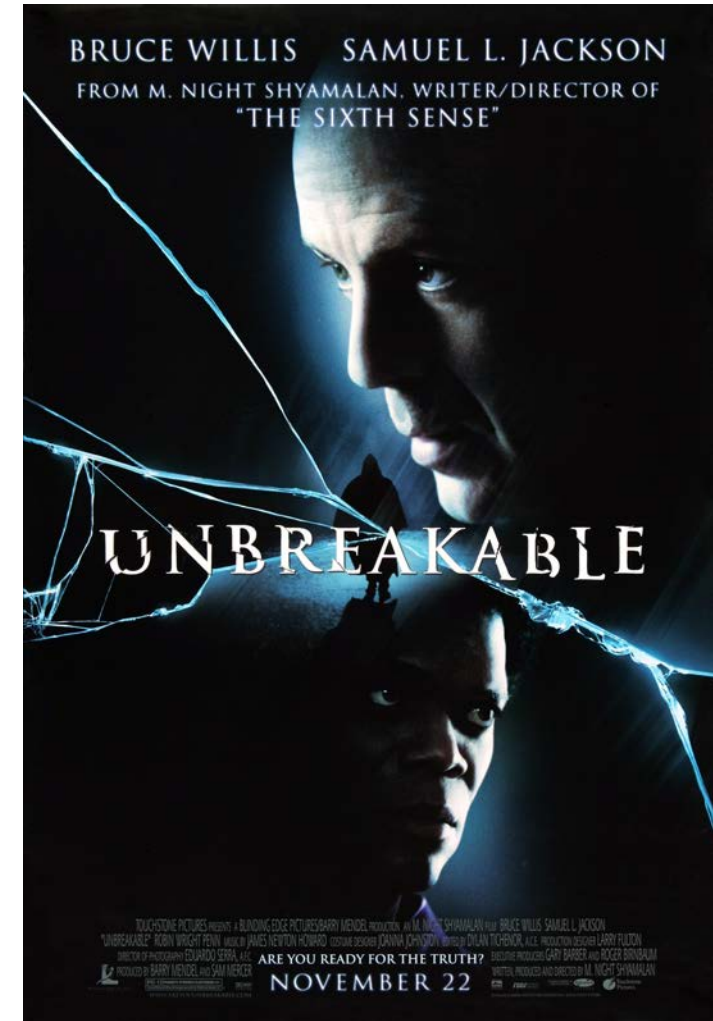


Weight agnostic neural networks

NeurIPS 2019, Inria / Google

Introduction (joke ☹)

- Movie “Unbreakable” (2000)
 - Mr. Glass vs David Dunn
- Neural networks are sensitive to their parameters...

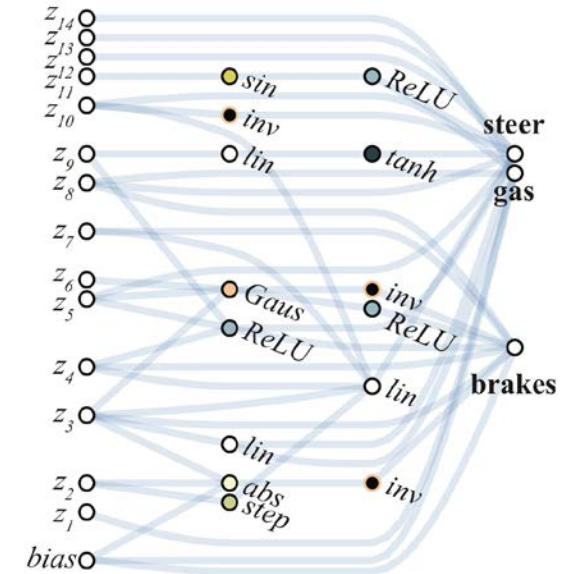
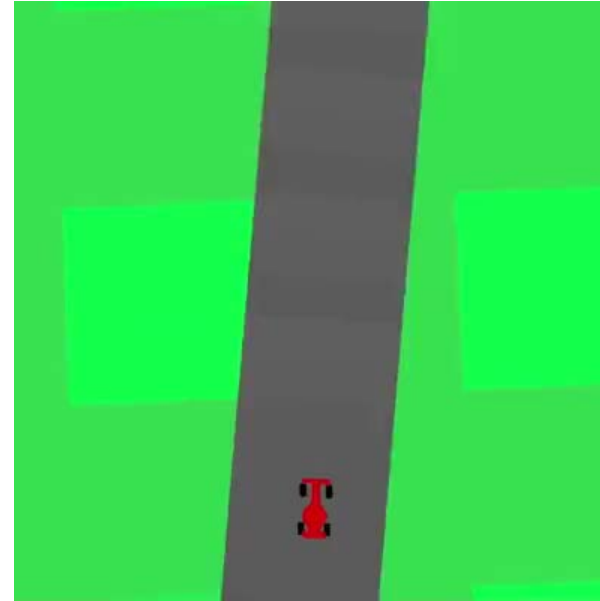
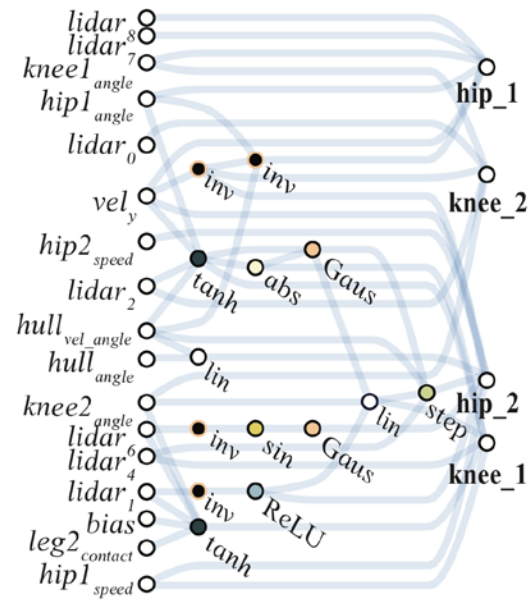
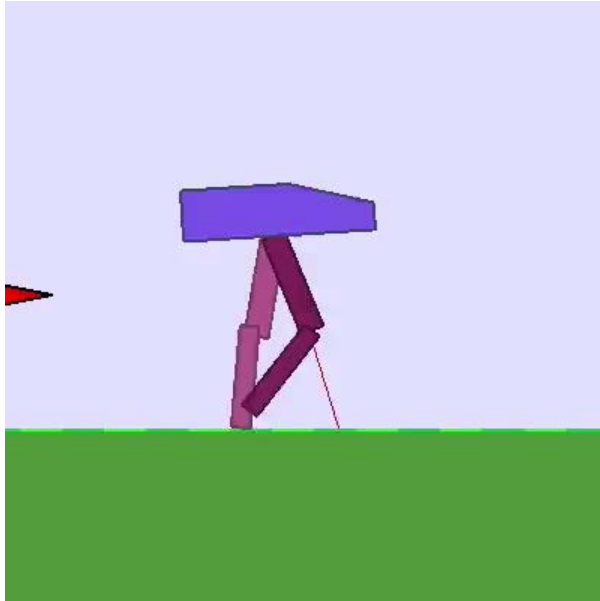


Question

- Not all neural network architectures are created equal, some perform much better than others for certain tasks
 - Is there a network that can already perform a task without any explicit weight training?
 - Is there a network architecture born to accomplish a certain task without training?
 - ...
- The answer is “yes”, but how can we find it?

Example

- Demo: <https://weightagnostic.github.io/>



- Bipedal Walker (left) and Car Racing (right)

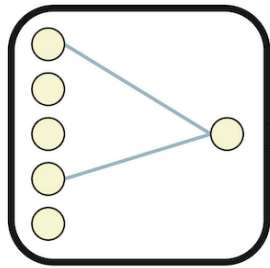
Problem setup

- Weight agnostic neural networks (WANNs) for a given task
 - An initial population of minimal neural network topologies is created
 - Each network is evaluated over multiple rollouts, with a different weight value
 - Weight-sharing on all weights; the number of parameter is one
 - Networks are ranked according to their average performance and complexity
 - A new population is created by varying the highest ranked network topologies
 - Repeat procedures above

Problem setup

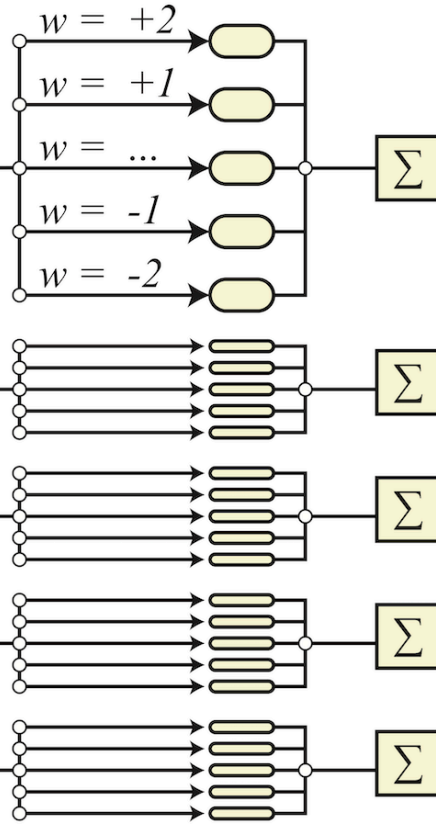
1.) Initialize

Create population of minimal networks.



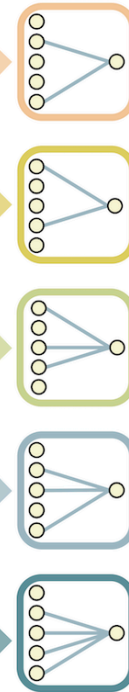
2.) Evaluate

Test with range of shared weight values.



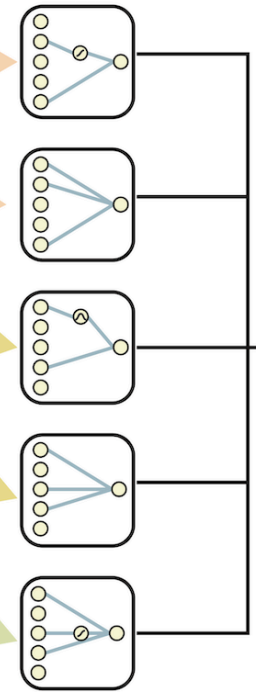
3.) Rank

Rank by performance and complexity



4.) Vary

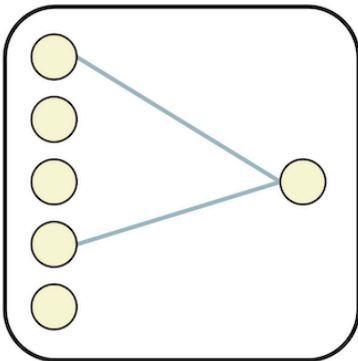
Create new population by varying best networks.



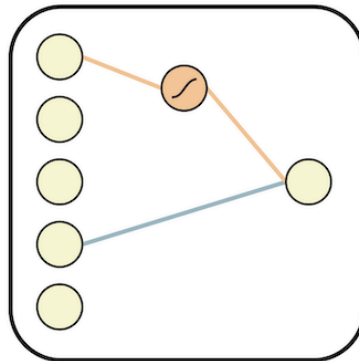
Topology search

- NeuroEvolution of Augmenting Topologies (NEAT)
 - The initial population is composed of sparsely connected networks
 - Networks with no hidden nodes and only a fraction of the possible connection between input and output
 - New networks are created by modifying existing networks using one of three operators
 - Insert node / Add connection / Change activation

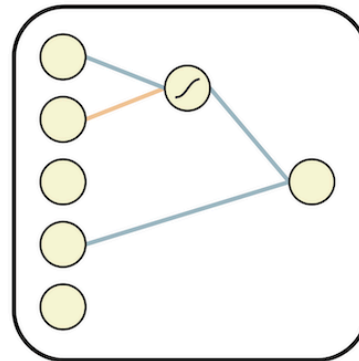
Minimal Network



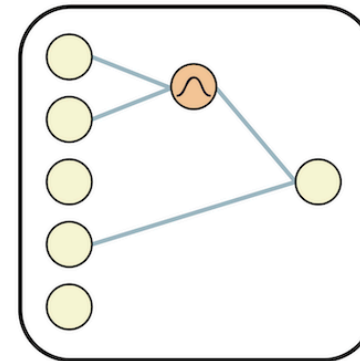
Insert Node



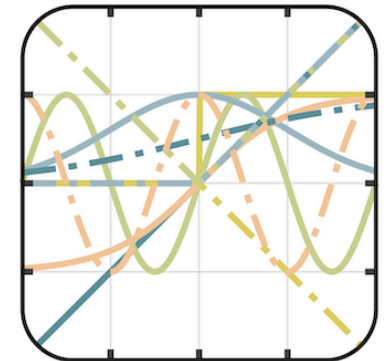
Add Connection



Change Activation



Node Activations



Performance and complexity

- Performance
 - Network topologies are evaluated using several shared weight values
 - $[-2, -1, -0.5, +0.5, +1, +2]$
 - Mean performance over all weight values
 - Max performance on the single best weight value
- Complexity
 - Minimal description length (MDL) → Occam's razor
 - Number of connections in the network
- Ranking
 - 80%: mean performance / number of connections
 - 20%: mean performance / max performance

Experimental results

- Continuous control
 - CartPoleSwingUp / BipedalWalker-v2 / CarRacing-v0
- Mean performance over 100 trials under 4 conditions:
 - Random weight: individual weights drawn from $U(-2,2)$
 - Random shared weight: a single shared weight drawn from $U(-2,2)$
 - Tuned shared weight: the highest performing shared weight in $[-2,2]$
 - Tuned weight: individual weights tuned using population-based REINFORCE

Experimental results

| Swing Up | Random Weights | Random Shared Weight | Tuned Shared Weight | Tuned Weights |
|------------------|--------------------------------|---------------------------------|---------------------------------|--------------------------------|
| WANN | 57 ± 121 | 515 ± 58 | 723 ± 16 | 932 ± 6 |
| Fixed Topology | 21 ± 43 | 7 ± 2 | 8 ± 1 | 918 ± 7 |
| Biped | Random Weights | Random Shared Weight | Tuned Shared Weight | Tuned Weights |
| WANN | -46 ± 54 | 51 ± 108 | 261 ± 58 | 332 ± 1 |
| Fixed Topology | -129 ± 28 | -107 ± 12 | -35 ± 23 | 347 ± 1 |
| CarRacing | Random Weights | Random Shared Weight | Tuned Shared Weight | Tuned Weights |
| WANN | -69 ± 31 | 375 ± 177 | 608 ± 161 | 893 ± 74 |
| Fixed Topology | -82 ± 13 | -85 ± 27 | -37 ± 36 | 906 ± 21 |

Experimental results

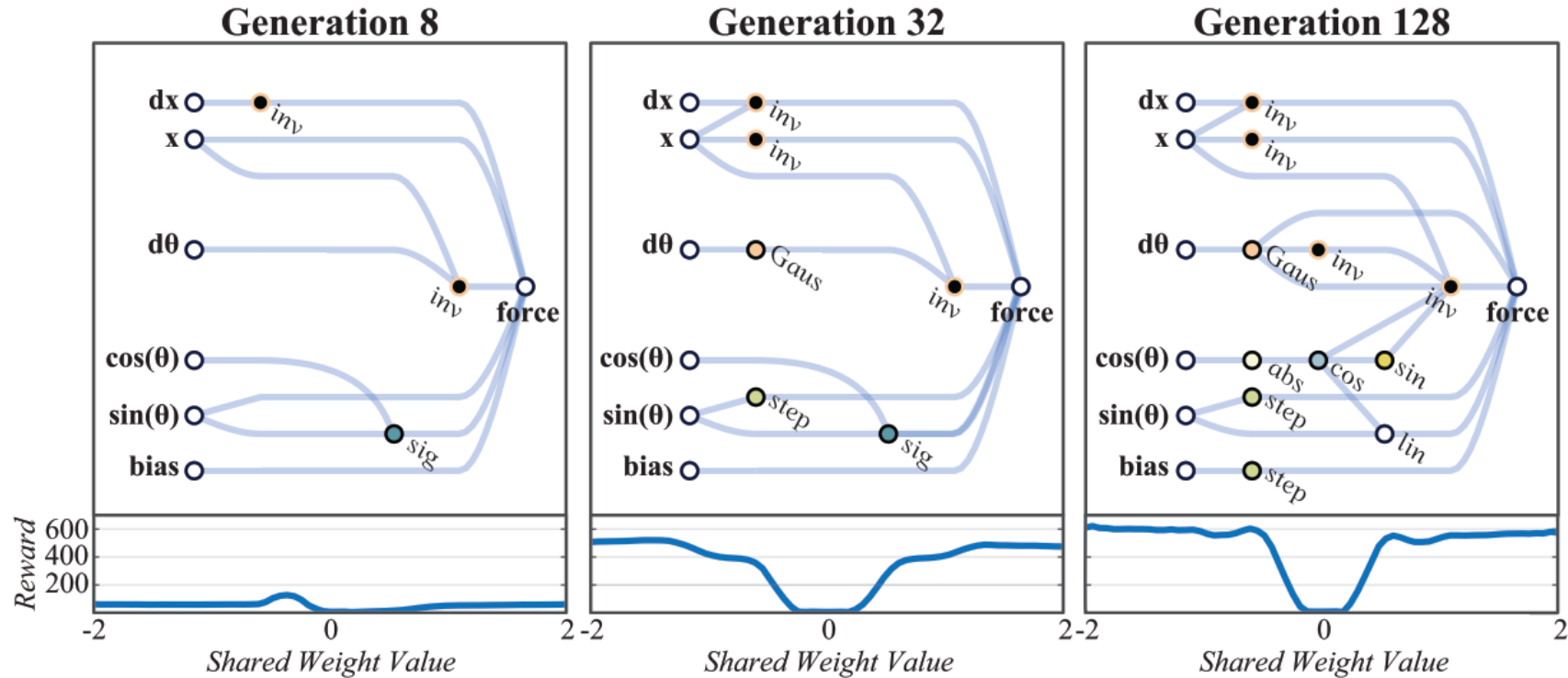


Figure 4: *Development of Weight Agnostic Neural Network Topologies Over Time*

Generation 8: An early network which performs poorly with nearly all weights.

Generation 32: Relationships between the position of the cart and velocity of the pole are established. The tension between these relationships produces both centering and swing-up behavior.

Generation 128: Complexity is added to refine the balancing behavior of the elevated pole.

Experimental results

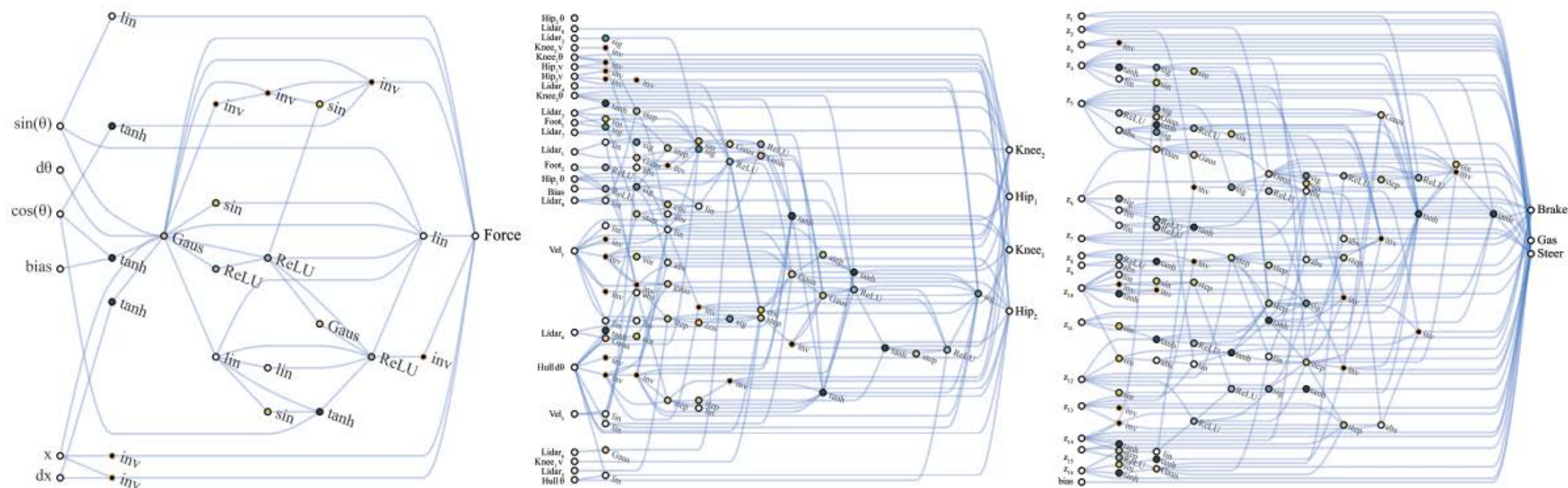


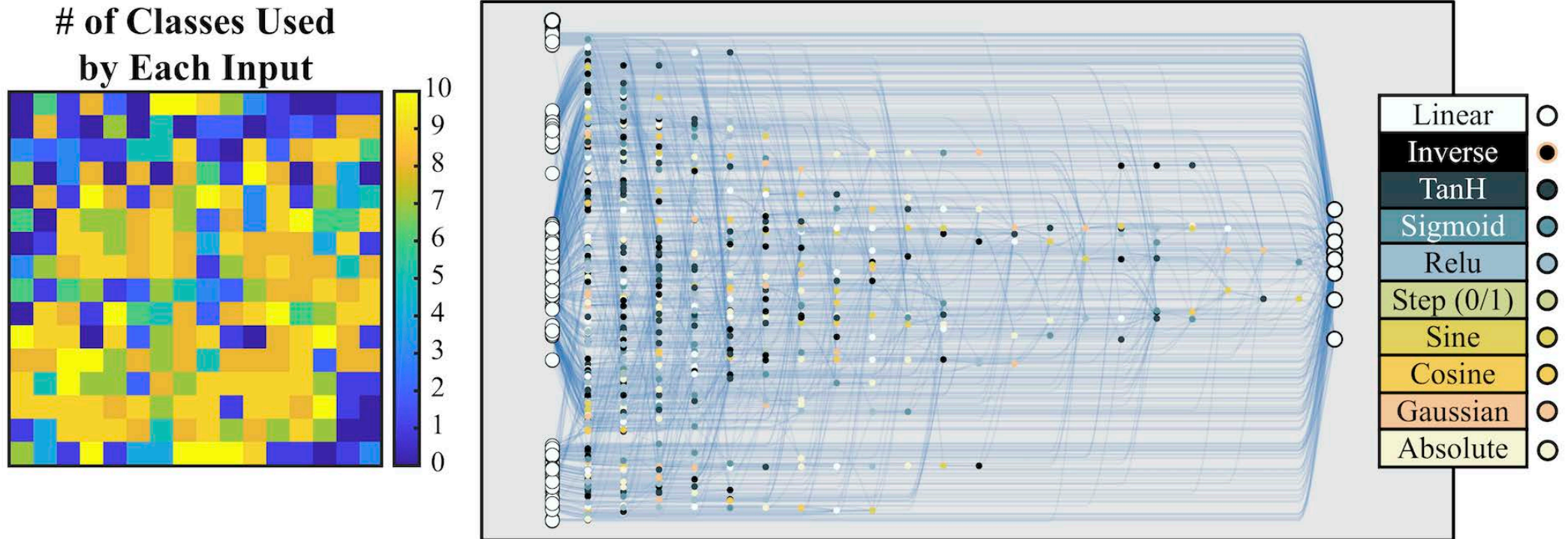
Figure 5: *Champion Networks for Continuous Control Tasks*

Left to Right (Number of Connections): Swing up (52), Biped (210), Car Racing (245)

Shown in Figure 1 (Page 1) are high performing, but simpler networks, chosen for clarity. The three network architectures in this figure describe the champion networks whose results are reported.

Experimental results

- Classification accuracy on MNIST

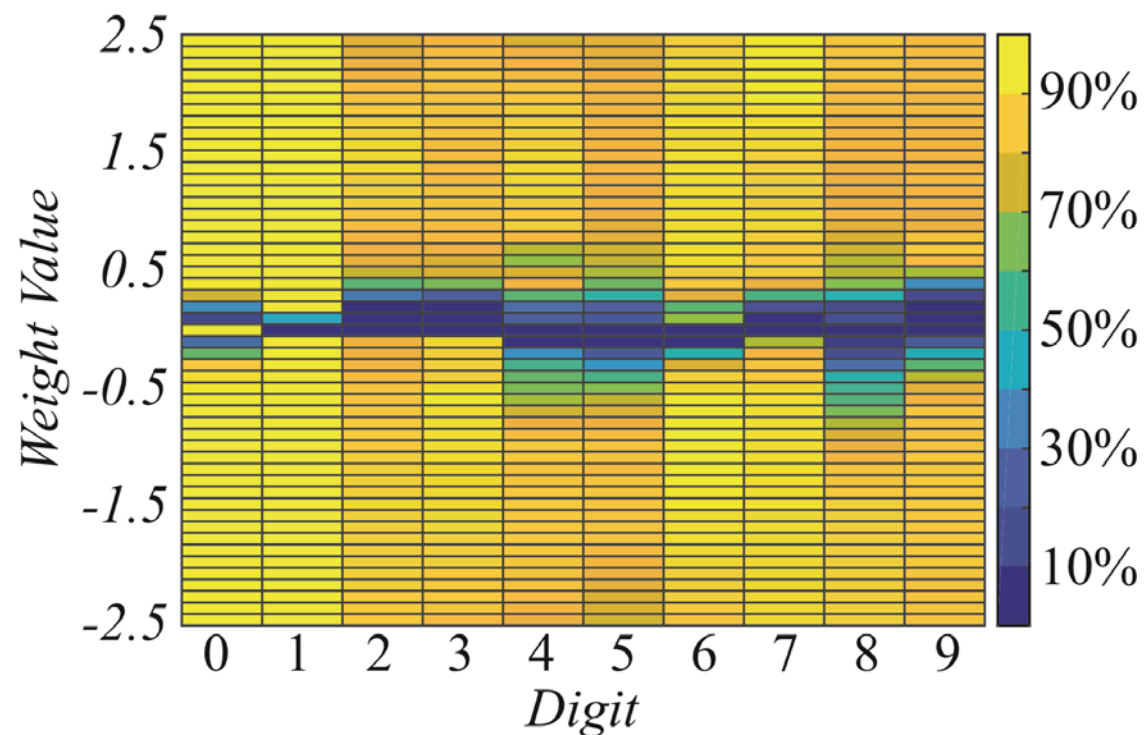


Experimental results

- Classification accuracy on MNIST

| WANN | Test Accuracy |
|------------------|---------------------|
| Random Weight | $82.0\% \pm 18.7\%$ |
| Ensemble Weights | 91.6% |
| Tuned Weight | 91.9% |
| Trained Weights | 94.2% |

| ANN | Test Accuracy |
|-------------------|---------------|
| Linear Regression | 91.6% [62] |
| Two-Layer CNN | 99.3% [15] |



Discussion

- Weight agnostic neural network and natural / eigen parameters
- Neuroscience
 - *Animal behavior is innate, and does not arise from learning*
 - Born to ~~~~ / born to be ~~~~