# Challenge 5: Transference

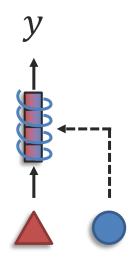
### **Transference**

**Definition:** Transfer knowledge between modalities, usually to help the primary modality which may be noisy or with limited resources

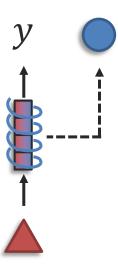
#### **Sub-challenges:**

**Transfer** 

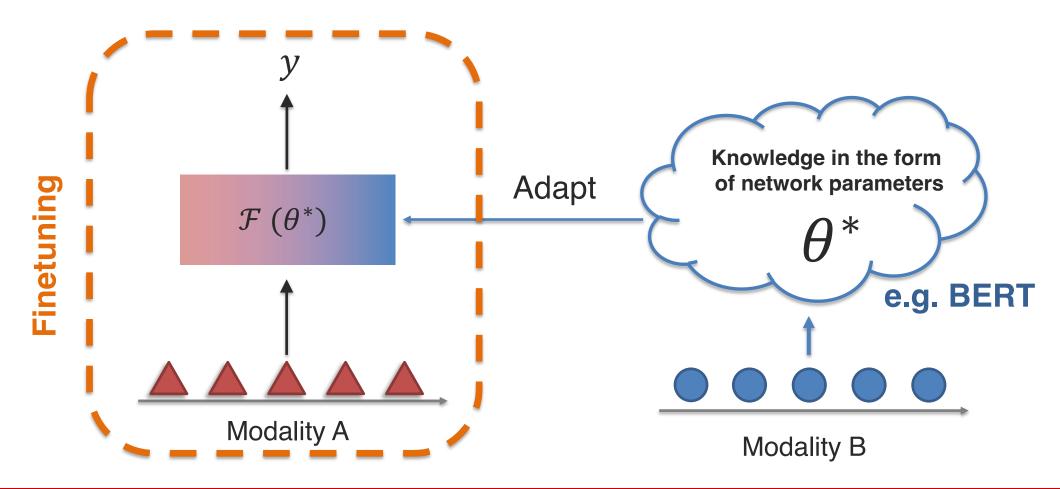




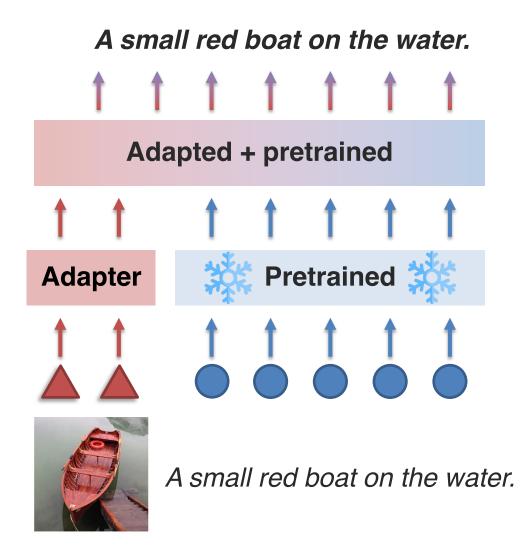
## Co-learning via generation



**Definition:** Transferring knowledge from large-scale pretrained models to downstream tasks involving the primary modality.



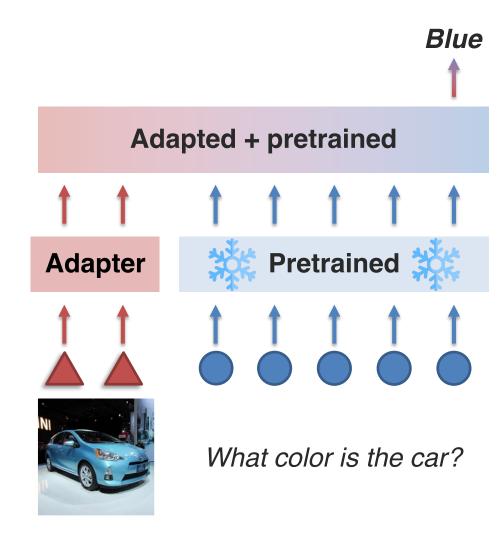
**Transfer via prefix tuning** 



[Tsimpoukelli et al., Multimodal Few-Shot Learning with Frozen Language Models. NeurIPS 2021]

### Transfer via prefix tuning

0-shot VQA:



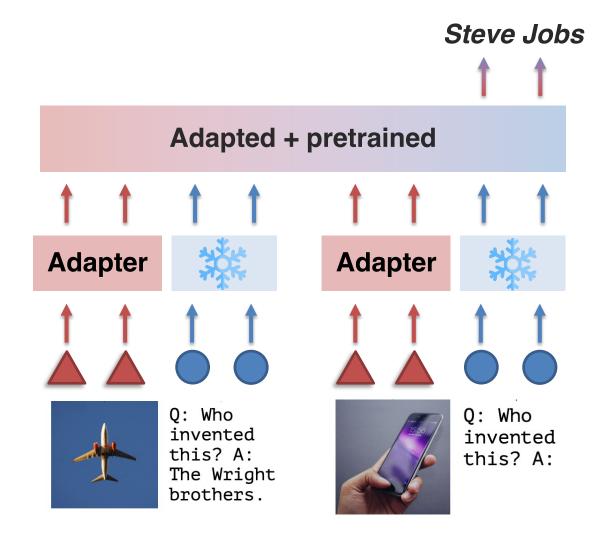
[Tsimpoukelli et al., Multimodal Few-Shot Learning with Frozen Language Models. NeurIPS 2021]

#### Transfer via prefix tuning

1-shot outside knowledge VQA:

Recall reasoning

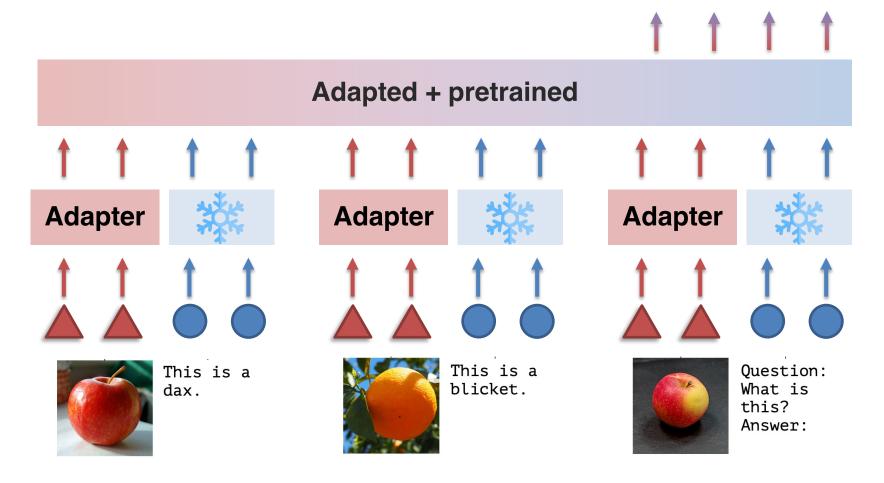
– leverage implicit
knowledge in LMs



[Tsimpoukelli et al., Multimodal Few-Shot Learning with Frozen Language Models. NeurIPS 2021]

Transfer via prefix tuning

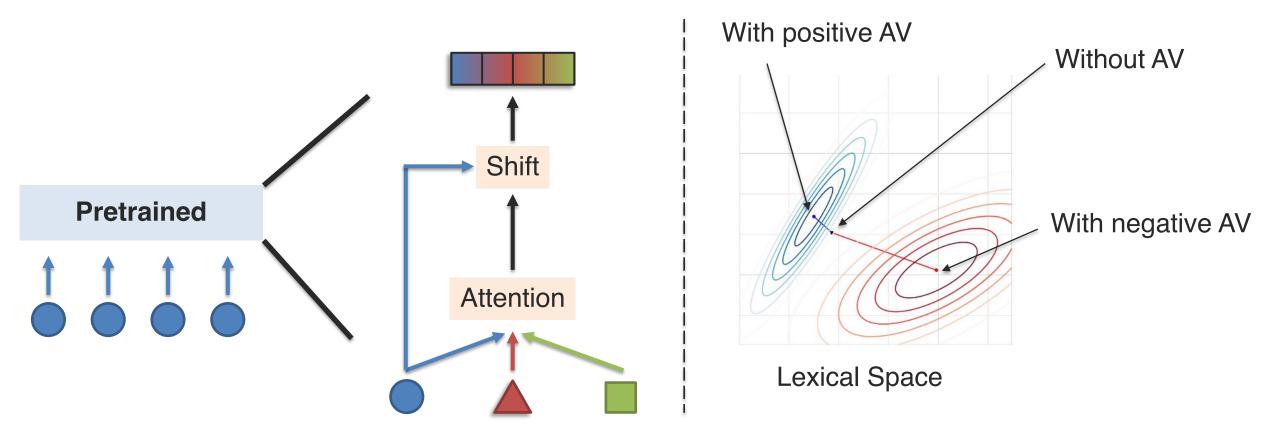
Few-shot image classification:



[Tsimpoukelli et al., Multimodal Few-Shot Learning with Frozen Language Models. NeurIPS 2021]

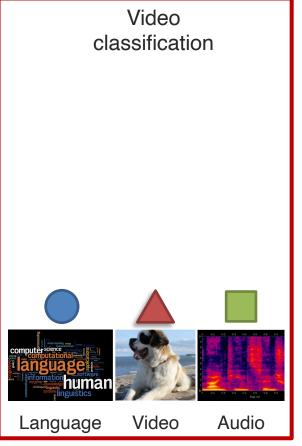
This is a dax.

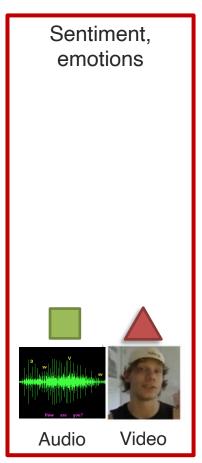
#### Transfer via representation tuning



[Ziegler et al., Encoder-Agnostic Adaptation for Conditional Language Generation. arXiv 2019] [Rahman et al., Integrating Multimodal Information in Large Pretrained Transformers. ACL 2020]

How can we transfer knowledge across multiple tasks, each over a different subset of modalities?





Video Time-series

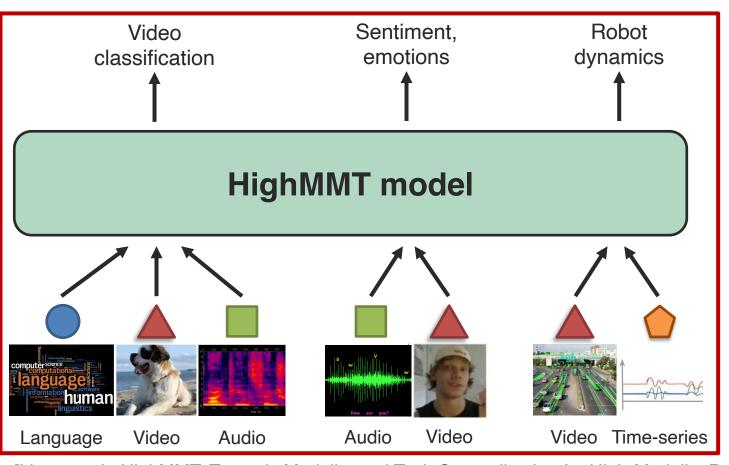
Robot

dynamics

Generalization across modalities and tasks Important if some tasks are low-resource

#### Transfer across partially observable modalities

HighMMT: unified model + parameter sharing + multitask and transfer learning



Non-parallel multitask learning

**Task-specific classifiers** 

Shared multimodal model

Same model architecture!

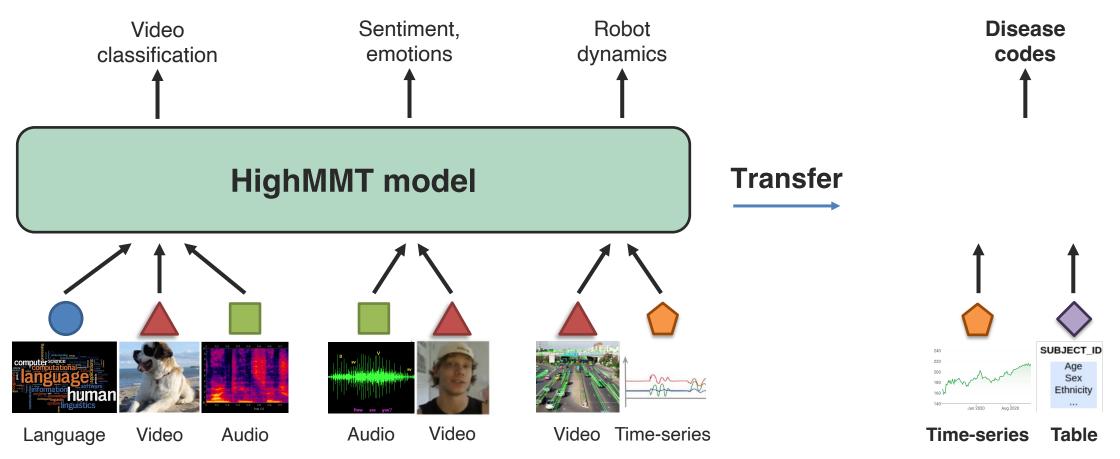
Same parameters!

**Modality-specific embeddings** 

Standardized input sequence

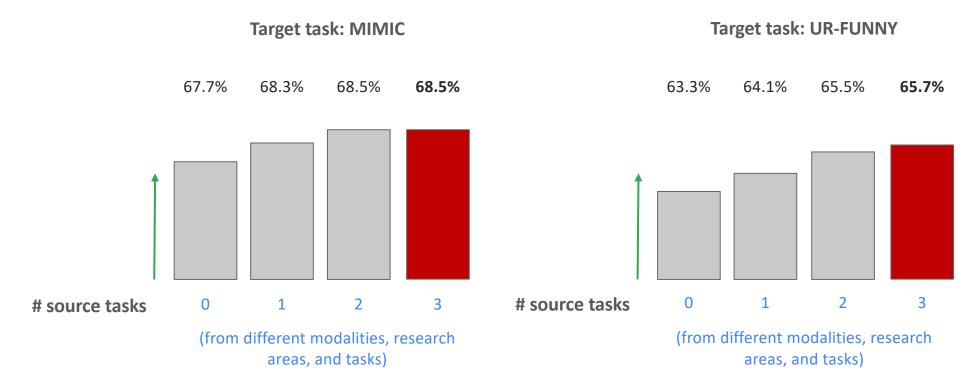
#### Transfer across partially observable modalities

HighMMT: unified model + parameter sharing + multitask and transfer learning



#### Transfer across partially observable modalities

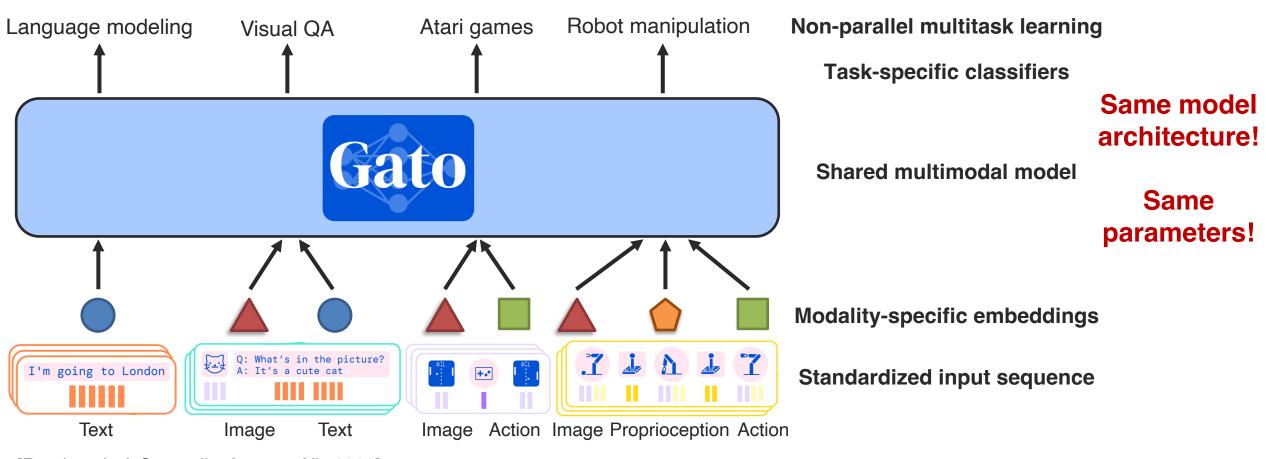
HighMMT: unified model + parameter sharing + multitask and transfer learning



Achieves both multitask and transfer capabilities across modalities and tasks

#### Transfer across partially observable modalities

Gato: unified model + parameter sharing + multitask learning

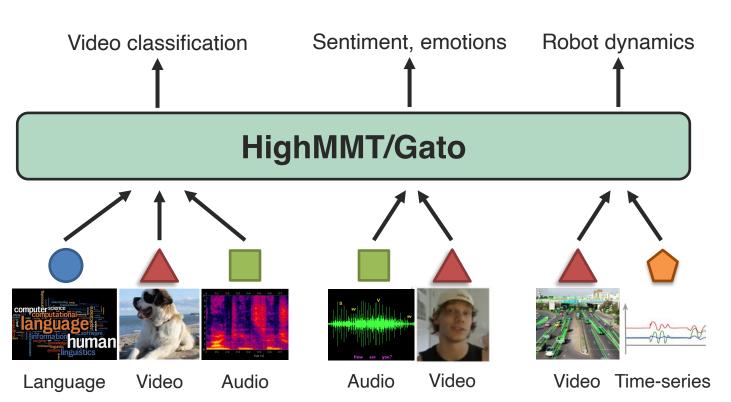


[Reed et al., A Generalist Agent. arXiv 2022]



#### Some implicit assumptions:

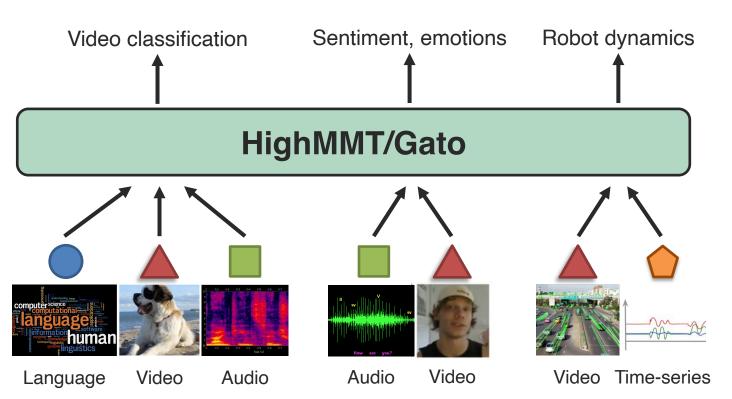
- All modalities can be represented as sequences without losing information



**Standardized input sequence?** 

#### Some implicit assumptions:

- All modalities can be represented as sequences without losing information
- Dimensions of heterogeneity can be perfectly captured by modality-specific embeddings

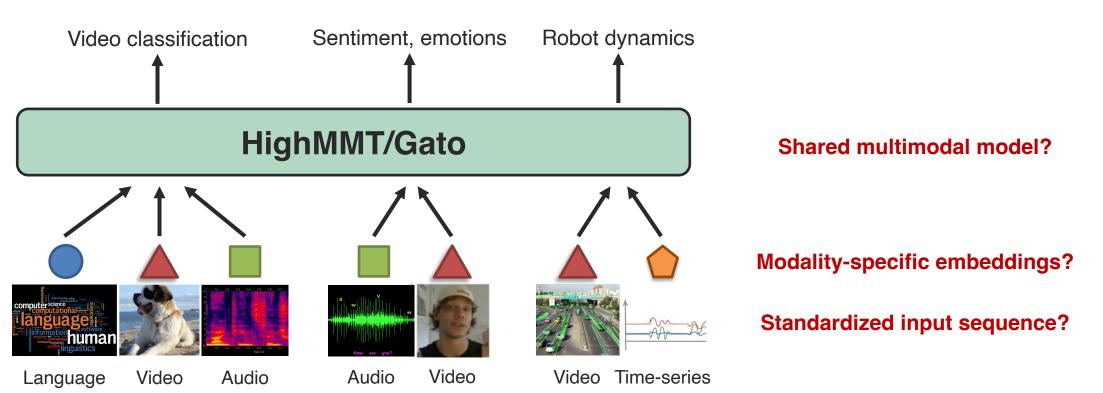


**Modality-specific embeddings?** 

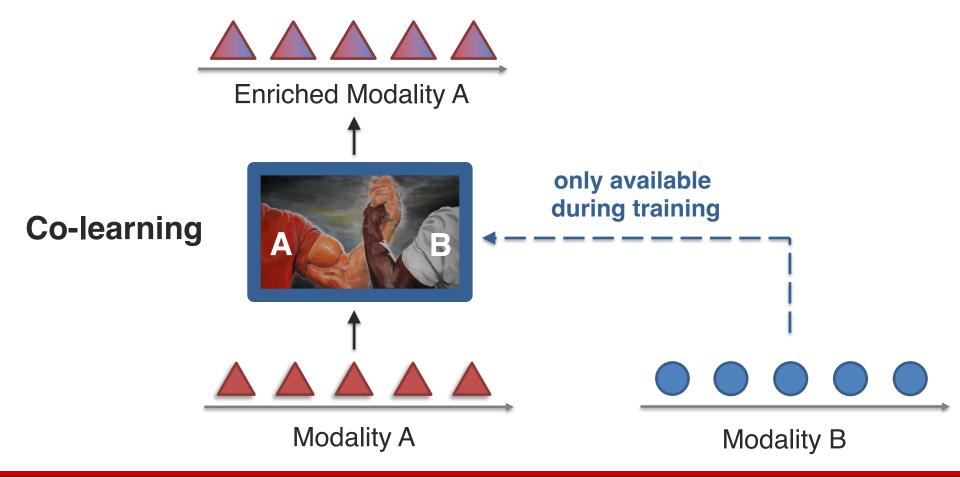
**Standardized input sequence?** 

#### Some implicit assumptions:

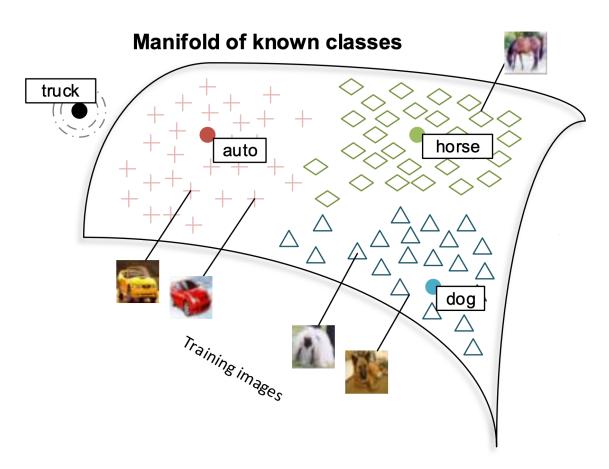
- All modalities can be represented as sequences without losing information
- Dimensions of heterogeneity can be perfectly captured by modality-specific embeddings
- Cross-modal connections & interactions are shared across modalities and tasks



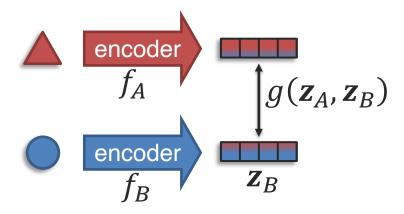
**Definition:** Transferring information from secondary to primary modality by sharing representation spaces between both modalities.



Representation coordination: word embedding space for zero-shot visual classification

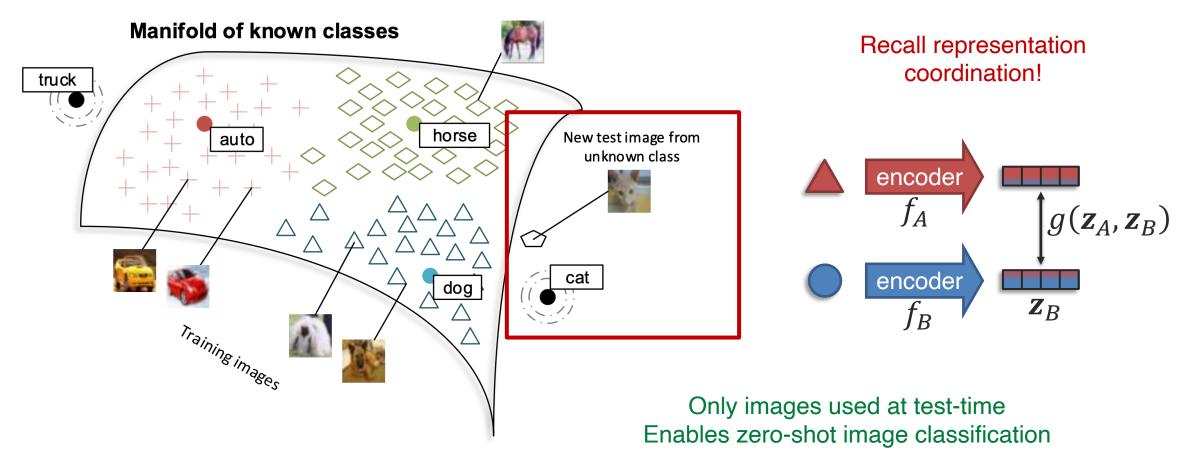


Recall representation coordination!



[Socher et al., Zero-Shot Learning Through Cross-Modal Transfer. NeurIPS 2013]

Representation coordination: word embedding space for zero-shot visual classification



[Socher et al., Zero-Shot Learning Through Cross-Modal Transfer. NeurIPS 2013]

#### **Representation fusion**

#### Multimodal co-learning

**Unimodal learning** 

Train Multimodal data
Multimodal model

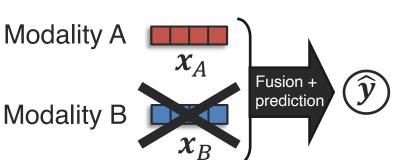
Modality A  $x_A$  Fusion + prediction  $\widehat{y}$  Modality B  $x_B$ 

Test

Language-only data

Language-only model

Fill rest by 0s



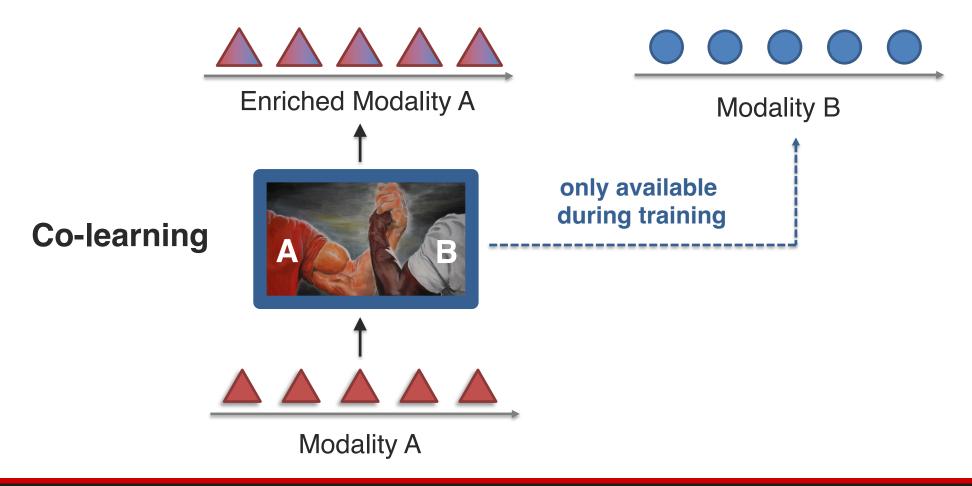
Only text used at test-time

Multimodal co-learning > language-only training

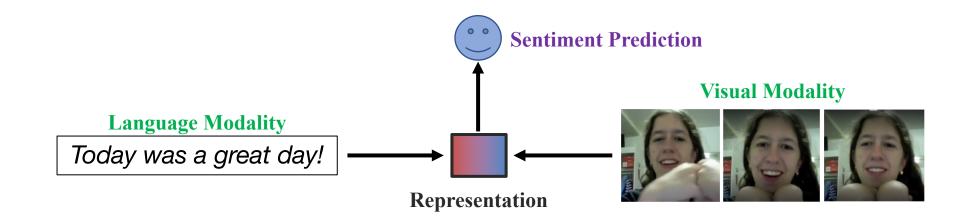
Fusion Modality A prediction  $x_A$ Fusion -Modality A prediction

[Zadeh et al., Foundations of Multimodal Co-learning. Information Fusion 2020]

**Definition:** Transferring information from secondary to primary modality by using the secondary modality as a generation target.



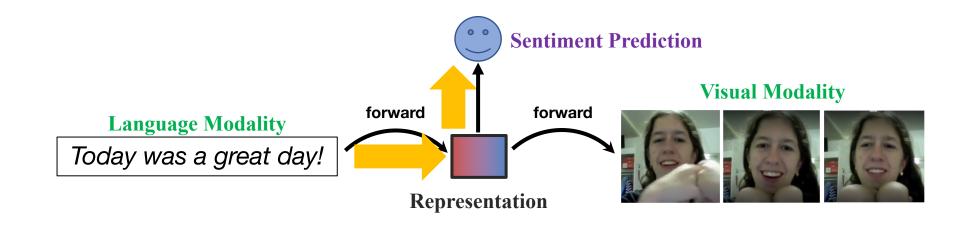
#### **Bimodal translations**



Both modalities required at test time! Sensitive to noisy/missing visual modality.

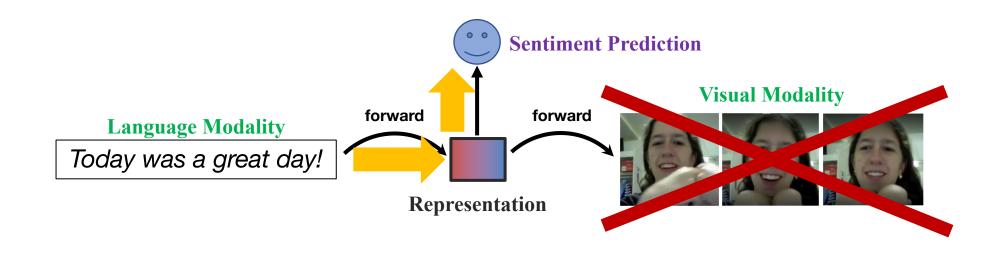
We want to leverage information from visual modality while being robust to it during test-time.

#### **Bimodal translations**



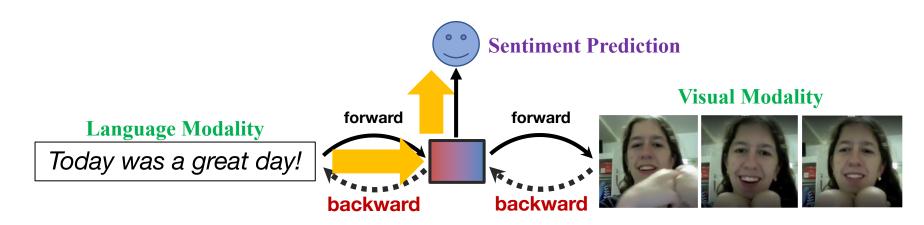
Cross-modal translation during training
Only language modality required at test time!

#### **Bimodal translations**



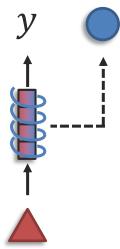
Problem: how do you ensure that both modalities are being used?

#### **Bimodal cyclic translations**



Solution: cyclic translations from visual back to language

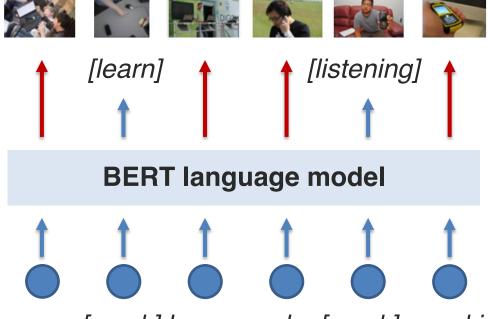
Cross-modal translation during training
Only language modality required at test time!



#### Predicting images from corresponding language

Voken (visual token) classification

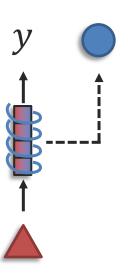
Masked language modeling



Humans [mask] language by [mask] speaking

Only text used at test-time

Multimodal co-learning > language-only training



[Tan and Bansal, Vokenization: Improving Language Understanding with Contextualized, Visual-Grounded Supervision. EMNLP 2020]

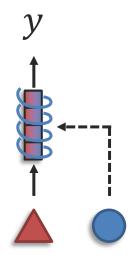
## **Summary: Transference**

**Definition:** Transfer knowledge between modalities, usually to help the primary modality which may be noisy or with limited resources.

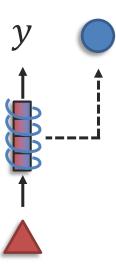
#### **Sub-challenges:**

**Transfer** 

## Co-learning via representation



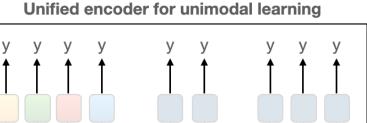
## Co-learning via generation



#### **More Transference**

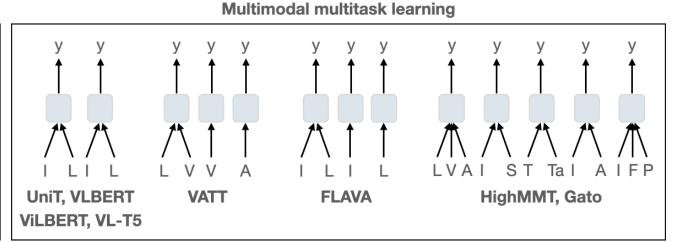


#### Many more dimensions of transfer



MultiModel

**ViT-BERT** 



I: image
V: video
A: audio
S: set
L: language
T: time-series
Ta: tables
F: force sensor
P: proprioception sensor

common architecture

parameter sharing

#### **Open challenges:**

Perceiver

- Low-resource: little downstream data, lack of paired data, robustness (next section)
- Beyond language and vision
- Settings where SOTA unimodal encoders are not deep learning e.g., tabular data
- Complexity in data, modeling, and training

**PolyViT** 

Interpretability (next section)