

Bayesian Additive Regression Trees using Gaussian Processes



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ArXiv paper:



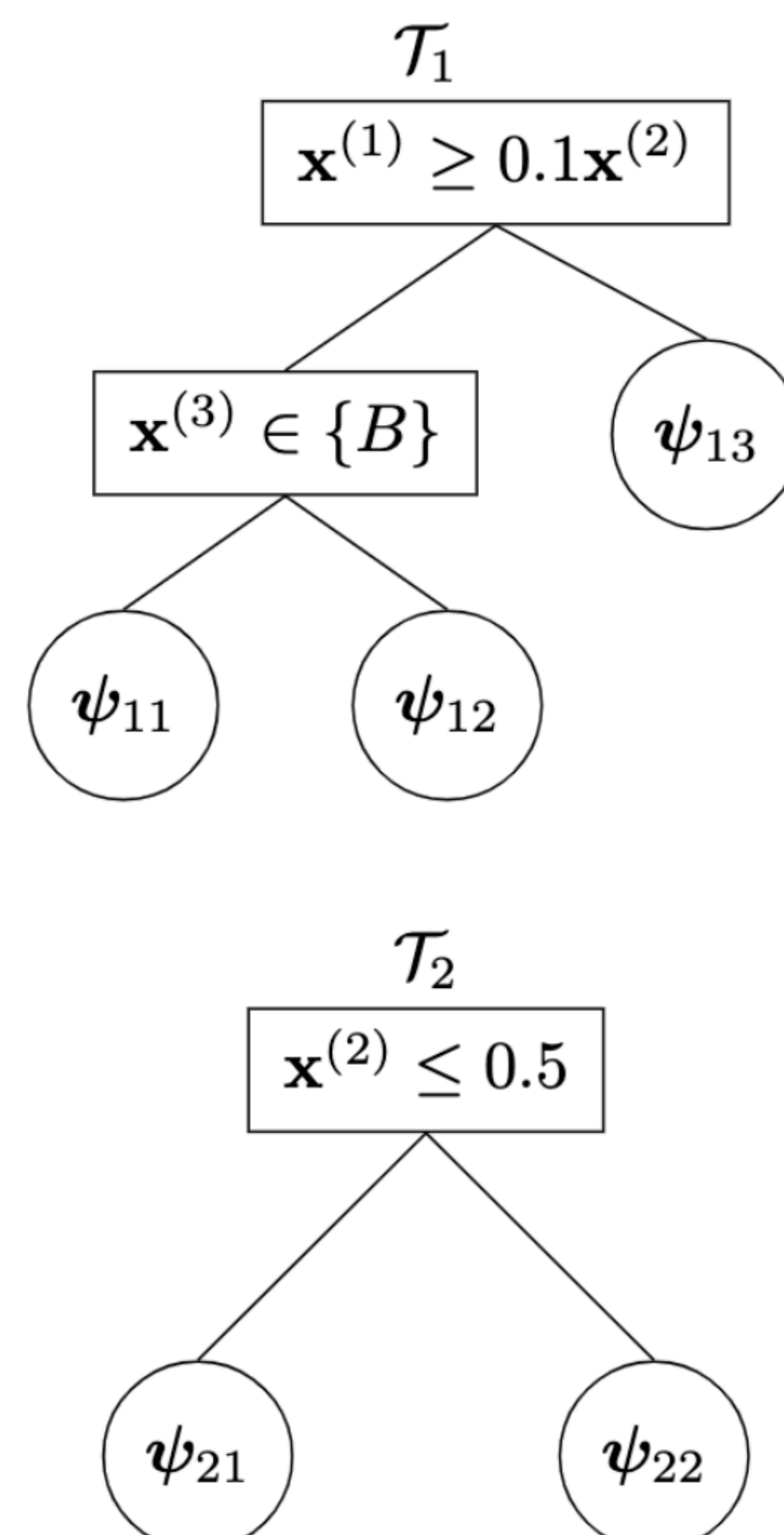
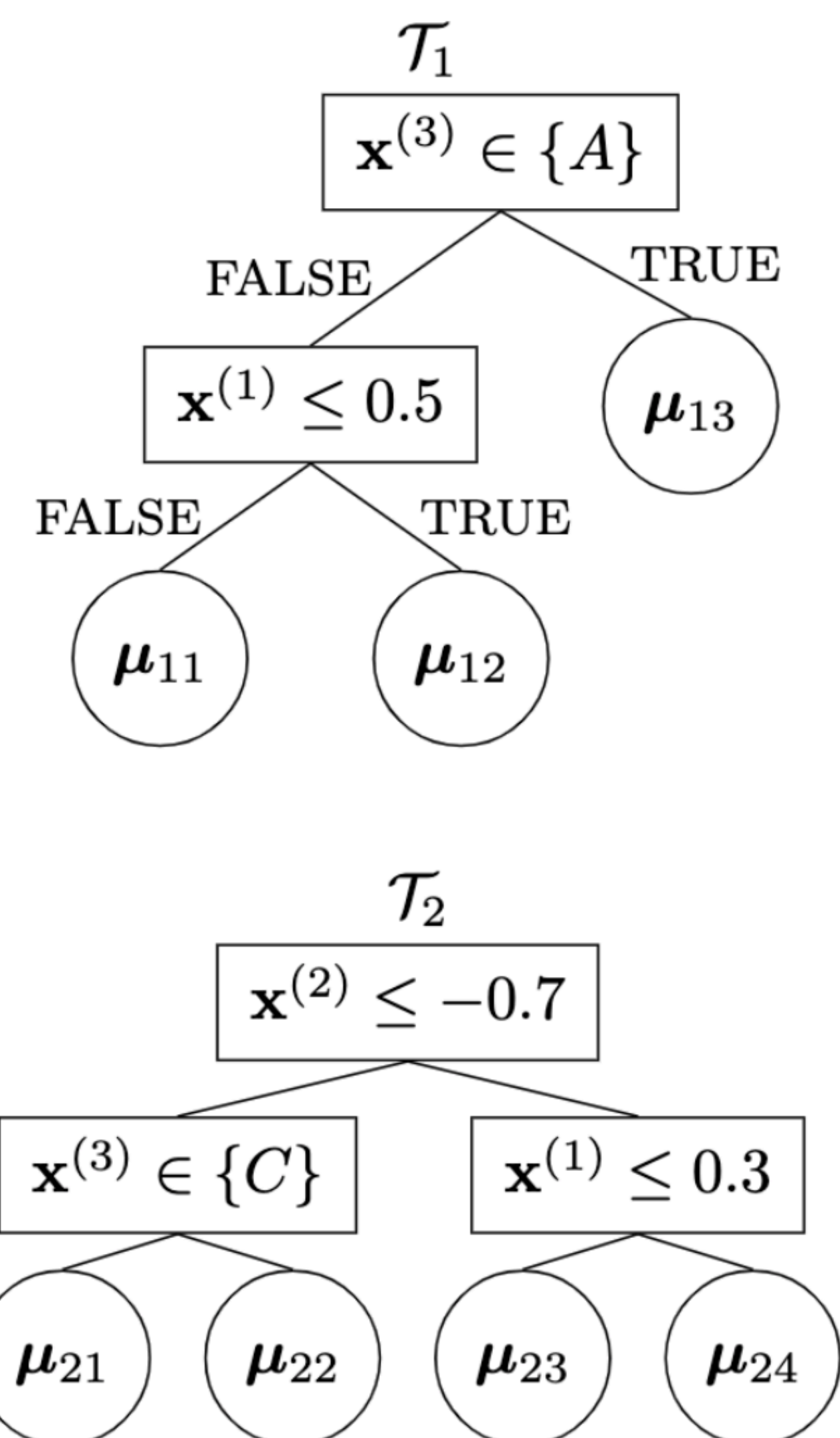
The problem

The Bayesian additive regression trees (BART) approach learns through a **sum of Bayesian trees**, where each terminal node's mean parameter $\mu_{t\ell}$ is constrained by a **regularising prior distribution**. The model is described by:

$$y_i | \mathbf{x}_i \sim N \left(\sum_{t=1}^T h(\mathbf{x}_i; \mathcal{T}_t, \mathbf{L}_t), \tau^{-1} \right)$$

The vector $\mathbf{L}_t = (\mu_{t1}, \dots, \mu_{tb_t})$ collects all mean parameters $\mu_{t\ell}$ from a tree \mathcal{T}_t and the function h assigns it to an observation \mathbf{x}_i that belongs to a terminal node ℓ .

This assignment of a single predicted value for all observations sharing a terminal node introduces a **stepwise-continuous** nature, such that the estimated functions from BART are generally **non-smooth**.



On the left, graphical representation of two example trees from a BART model. On the right, the graphical representation for GP-BART trees, with a GP prior $\psi_{t\ell}$ at the terminal node level.

The solution

The main contribution of this work is to define a **Gaussian process (GP) prior** in the terminal nodes.

$$\psi_{t\ell} | \mathcal{T}_t, \mu_{t\ell}, \phi_t, \nu \sim \text{GP} \left(\mu_{t\ell} = \mu_{t\ell} \mathbf{1}_{n_{t\ell}}, \nu^{-1} \exp \left\{ -\frac{1}{2} \sum_{j=1}^p \frac{(x_i^{(j)} - x_k^{(j)})^2}{\phi_{ij}^2} \right\} \right)$$

- To prevent any single tree from dominating the ensemble, the ν parameter fixes the GP's precision at $\nu = 8\kappa^2 T$, which regularises all trees.
- A gamma prior over the length parameters ϕ_{ij} allows Automatic Relevance Determination (ARD) and variable selection within the GP.

The algorithm

Algorithm 1: GP-BART sampling algorithm

Input: $\mathbf{X}, \mathbf{y}, T, N_{\text{MCMC}}$, and all hyperparameters of the priors.

Initialise: T tree stumps, $\tau = 1$, and $\phi_{tj} = 1 \forall (t, j)$.

for iterations m from 1 to N_{MCMC} **do**

for trees t from 1 to T **do**

 Calculate the partial residuals \mathbf{R}_t ;

 Propose a new tree \mathcal{T}_t^* by a grow, grow-project, change,

 change-project, or prune move;

 Accept and update $\mathcal{T}_t = \mathcal{T}_t^*$ with probability

$$\gamma^*(\mathcal{T}_t, \mathcal{T}_t^*) = \min \left\{ 1, \frac{\pi(\mathbf{R}_t | \mathcal{T}_t^*, \phi_t, \nu, \tau_\mu, \tau) \pi(\mathcal{T}_t^*)}{\pi(\mathbf{R}_t | \mathcal{T}_t, \phi_t, \nu, \tau_\mu, \tau) \pi(\mathcal{T}_t)} \right\}.$$

for terminal nodes ℓ from 1 to b_t **do**

 Update $\psi_{t\ell}$ using Gibbs.

end

 Update ϕ_t using MH.

end

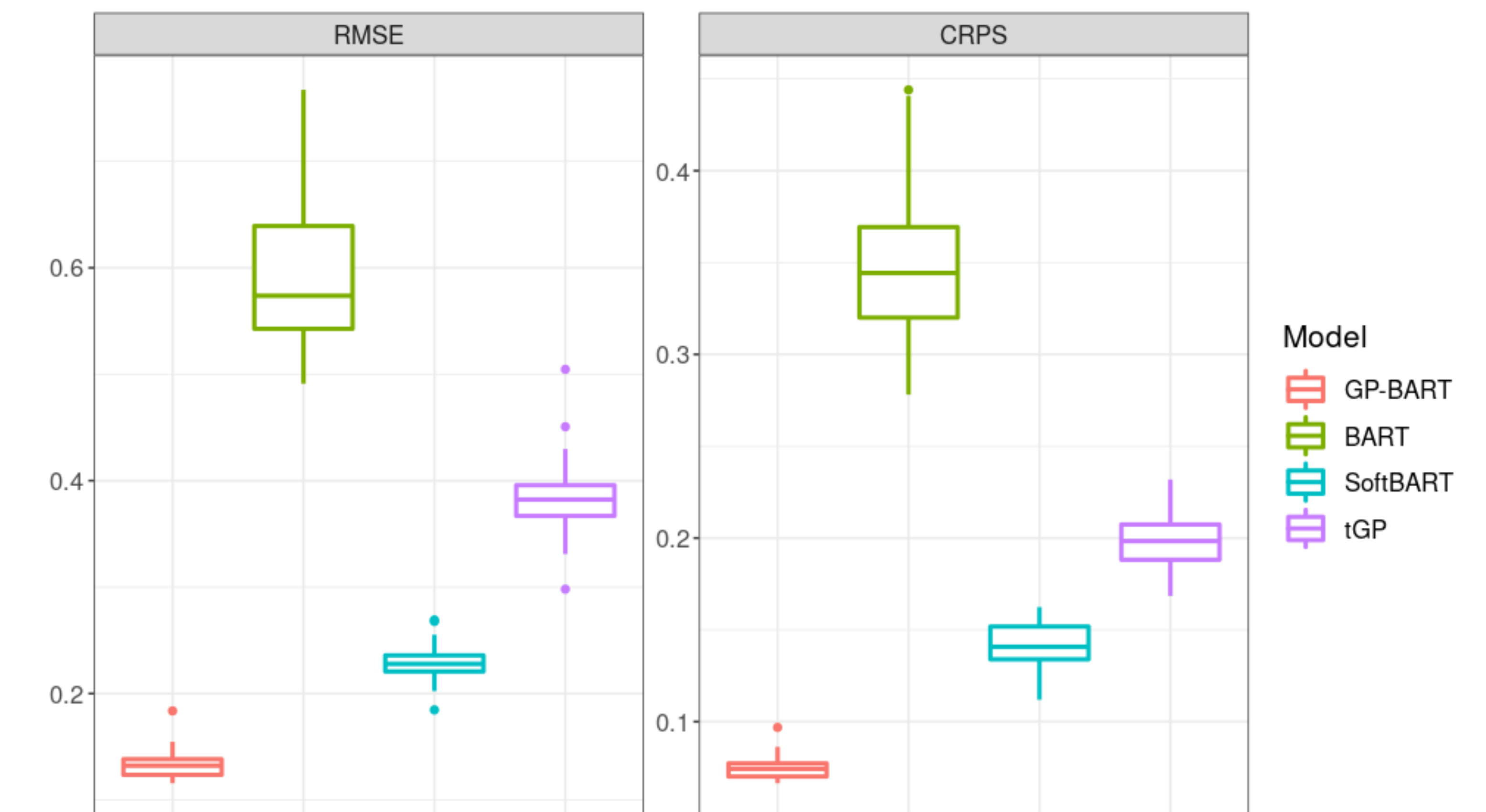
 Update τ using Gibbs.

end

Output: Posterior samples from $\pi((\mathcal{T}_1, \mathbf{G}_1), \dots, (\mathcal{T}_T, \mathbf{G}_T), \tau | \mathbf{y})$.

Results

- GP-BART was compared against other tree-based methods (BART, SoftBART, tGP).
- Simulation scenarios employed in the study used the Friedman data [1] with 5 additional noise variables.



Comparison of RMSE and CRPS over the 25 test folds from 5 repetitions of 5-fold cross-validation for the Friedman data set with $n = 500$ and $p = 10$.

- For a comparison using real data, four **spatial** datasets were analysed and GP-BART **outperformed** the competitors by presenting the lowest values of RMSE and CRPS in three of the four applications.
- Overall, GP-BART presents a promising extension of BART by imposing covariance structure to achieve **smoothness**.
- An R implementation of GP-BART is available at github.com/MateusMaiaDS/gpbart

References

[1] Friedman, Jerome H. "Multivariate adaptive regression splines." The Annals of Statistics 19.1 (1991): 1-67.

Acknowledgements

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