




Particle Learning of Gaussian Process Models for Sequential Design and Optimization

Robert B. Gramacy & Nicholas G. Polson


To cite this article: Robert B. Gramacy & Nicholas G. Polson (2011) Particle Learning of Gaussian Process Models for Sequential Design and Optimization, Journal of Computational and Graphical Statistics, 20:1, 102-118, DOI: [10.1198/jcgs.2010.09171](https://doi.org/10.1198/jcgs.2010.09171)

To link to this article: <https://doi.org/10.1198/jcgs.2010.09171>

 View supplementary material 

 Published online: 01 Jan 2012.

 Submit your article to this journal 

 Article views: 561

 View related articles 

 Citing articles: 19 View citing articles 



Supplementary materials for this article are available online.
Please click the JCGS link at <http://pubs.amstat.org>.

Particle Learning of Gaussian Process Models for Sequential Design and Optimization

Robert B. GRAMACY and Nicholas G. POLSON

We develop a simulation-based method for the online updating of Gaussian process regression and classification models. Our method exploits sequential Monte Carlo to produce a fast sequential design algorithm for these models relative to the established MCMC alternative. The latter is less ideal for sequential design since it must be restarted and iterated to convergence with the inclusion of each new design point. We illustrate some attractive ensemble aspects of our SMC approach, and show how active learning heuristics may be implemented via particles to optimize a noisy function or to explore classification boundaries online. Supplemental material, including an R package, is available online.

Key Words: Entropy; Expected improvement; Nonparametric regression and classification; Sequential Monte Carlo.

1. INTRODUCTION

The Gaussian process (GP) is by now well established as the backbone of many highly flexible and effective nonlinear regression and classification models (e.g., Neal 1998; Rasmussen and Williams 2006). One important application for GPs is in the sequential design of computer experiments (Santner, Williams, and Notz 2003) where designs are built up iteratively: choose a new design point x according to some criterion derived from a GP surrogate model fit; update the fit conditional on the new pair $(x, y(x))$; and repeat. The goal is to keep designs small in order to save on expensive simulations of $y(x)$. By “fit” we colloquially mean: samples obtained from the GP posterior via MCMC. While it is possible to choose each new design point via full utility-based design criteria (e.g., Müller, Sansó, and de Iorio 2004), this can be computationally daunting even for modestly sized designs. More thrifty *active learning* (AL) criteria such as ALM (MacKay 1992) and

Robert B. Gramacy is Assistant Professor of Econometrics and Statistics, Booth School of Business, University of Chicago, Chicago, IL 60637-1610 (E-mail: rbgramacy@chicagobooth.edu). Nicholas G. Polson is Professor of Econometrics and Statistics, Booth School of Business, University of Chicago, Chicago, IL 60637-1610 (E-mail: ngp@chicagobooth.edu). Most of this research was conducted while RBG was a Lecturer at the Statistical Laboratory, University of Cambridge, Cambridge, Cambridgeshire CB3 0WB, U.K.

© 2011 American Statistical Association, Institute of Mathematical Statistics,
and Interface Foundation of North America

Journal of Computational and Graphical Statistics, Volume 20, Number 1, Pages 102–118
DOI: 10.1198/jcgs.2010.09171

ALC (Cohn 1996) can be an effective alternative. These were first used with GPs by Seo et al. (2000), and have since been paired with a nonstationary GP to design a rocket booster (Gramacy and Lee 2009).

Similar AL criteria are available for other sequential design tasks. Optimization by *expected improvement* (EI, Jones, Schonlau, and Welch 1998) is one example. Taddy et al. (2009) used an embellished EI with a nonstationary GP model and MCMC inference to determine the optimal robust configuration of a circuit device. In the classification setting, characteristics like the predictive entropy (Joshi, Porikli, and Papanikolopoulos 2009) can be used to explore the boundaries between regions of differing class label in order to maximize the information obtained from each new x . The thrifty nature of AL and the flexibility of the GP is a favorable marriage, indeed. However, a drawback of batch MCMC-based inference is that it is not tailored to the online nature of sequential design. Except to guide the initialization of a new Markov chain, it is not clear how fits from earlier iterations may be reused in search of the next x . So after the design is augmented with $(x, y(x))$ the MCMC must be restarted and iterated to convergence.

In this article we propose to use a sequential Monte Carlo (SMC) technique called *particle learning* (PL) to exploit the analytically tractable (and Rao–Blackwellizable) GP posterior *predictive* distribution in order to obtain a quick update of the GP fit after each sequential design iteration. We then show how some key AL heuristics may be efficiently calculated from the particle approximation. Taken separately, SMC/PL, GPs, and AL are by now well-established techniques in their own right. Our contribution lies in illustrating how together they can be a potent mixture for sequential design and optimization under uncertainty.

The remainder of the article is outlined as follows. Section 1.1 describes the basic elements of GP modeling. Section 1.2 reviews SMC and PL, highlighting the strengths of PL in our setting. Section 2 develops a PL implementation for GP regression and classification, with illustrations and comparisons to MCMC. We show how fast updates of particle approximations may be used for AL in optimization and classification in Section 3, and we conclude with a discussion in Section 4. Software implementing our methods, and the specific code for our illustrative examples, is available in the `plgp` package (Gramacy 2010) for R on CRAN and as supplementary material online via *JCGS*.

1.1 GAUSSIAN PROCESS PRIORS FOR REGRESSION AND CLASSIFICATION

A GP prior for functions $Y : \mathbb{R}^p \rightarrow \mathbb{R}$, where any finite collection of outputs is jointly Gaussian (Stein 1999), is defined by its mean $\mu(x) = \mathbb{E}\{Y(x)\} = f(x)^\top \beta$ and covariance $C(x, x') = \mathbb{E}\{[Y(x) - \mu(x)][Y(x') - \mu(x')]^\top\}$. Often the mean is linear in the inputs ($f(x) = [1, x]$) and β is an unknown $(p+1) \times 1$ parameter vector. Typically, one separates out the variance σ^2 in $C(x, x')$ and works with correlations $K(x, x') = \sigma^{-2}C(x, x')$ based on Euclidean distance and a small number of unknown parameters (see, e.g., Abrahamsen 1997). In the classical inferential setting we may view the GP “prior” as a choice of model function, thus resembling a likelihood.

In the regression problem, the likelihood of data $D_N = (X_N, Y_N)$, where X_N is an $N \times p$ design matrix and Y_N is an $N \times 1$ response vector, is multivariate normal (MVN)

for Y_N with mean $\mu(X_N) = F_N\beta$, where F_N is an $N \times (p+1)$ matrix that contains $f(x_i)^\top$ in its rows, and covariance $\Sigma(X_N) = \sigma^2 K_N$, where K_N is the $N \times N$ covariance matrix with (ij) th entry $K(x_i, x_j)$. To reduce clutter, we shall drop the N subscript when the context is clear. Conditional on K , the MLE for β and σ^2 is available in closed form via weighted least squares. The profile likelihood may be used to infer the parameters to $K(\cdot, \cdot)$ numerically.

Bayesian inference may proceed by specifying priors over β , σ^2 , and the parameters to $K(\cdot, \cdot)$. With priors $\beta \propto 1$ and $\sigma^2 \sim \text{IG}(a/2, b/2)$, the marginal posterior distribution for $K(\cdot, \cdot)$, integrating over β and σ^2 , is available in closed form (Gramacy 2005, section A.2):

$$p(K|D) = p(K) \times \left(\frac{|V_\beta|}{|K|} \right)^{1/2} \times \frac{(b/2)^{a/2} \Gamma[(a+N-p)/2]}{(2\pi)^{(N-p)/2} \Gamma[a/2]} \\ \times \left(\frac{b+\psi}{2} \right)^{-(a+N-p)/2}, \quad (1.1)$$

$$\psi = Y^\top K^{-1} Y - \tilde{\beta}^\top V_\beta^{-1} \tilde{\beta}, \quad \tilde{\beta} = V_\beta (F^\top K^{-1} Y), \\ V_\beta = (F^\top K^{-1} F)^{-1}. \quad (1.2)$$

It is possible to use a vague scale-invariant prior ($a, b = 0$) for σ^2 . In this case, the marginal posterior (1.1) is proper as long as $N > p+1$. Mixing is generally good for Metropolis–Hastings (MH) sampling as long as $K(\cdot, \cdot)$ is parsimoniously parameterized, N is large, and there is a high signal-to-noise ratio between X and Y . Otherwise, the posterior can be multimodal (e.g., Warnes and Ripley 1987) and hard to sample.

Crucially for our SMC inference via PL (Section 2), and for our AL heuristics (Section 3), the fully marginalized predictive equations for GP regression are available in closed form. Specifically, the distribution of the response $Y(x)$ conditioned on data D and covariance $K(\cdot, \cdot)$, that is, $p(y(x)|D, K)$, is Student- t with degrees of freedom $\hat{v} = N - p - 1$,

$$\text{mean: } \hat{y}(x|D, K) = f(x)^\top \tilde{\beta} + k^\top(x) K^{-1} (Y - F \tilde{\beta}) \quad (1.3)$$

and

$$\text{scale: } \hat{\sigma}^2(x|D, K) = \frac{(b+\psi)[K(x, x) - k^\top(x) K^{-1} k(x)]}{a + \hat{v}}, \quad (1.4)$$

where $k^\top(x)$ is the N -vector whose i th component is $K(x, x_i)$.

In the classification problem, with data $D = (X, C)$, where C is an $N \times 1$ vector of class labels $c_i \in \{1, \dots, M\}$, the GP is used M -fold as a prior over a collection of $M \times N$ latent variables $\mathcal{Y} = \{Y_{(m)}\}_{m=1}^M$, one set for each class. For a particular class m , the generative model (or prior) over the latent variables is MVN with mean $\mu_{(m)}(X)$ and variance $\Sigma_{(m)}(X)$, as in the regression setup. The class labels then determine the likelihood through the latent variables under an independence assumption so that $p(C_N|\mathcal{Y}) = \prod_{i=1}^N p_i$, where $p_i = p(C(x_i) = c_i|\mathcal{Y}_i)$. Neal (1998) recommended a *softmax* specification:

$$p(c|y_{(1:M)}) = \frac{\exp\{-y_{(c)}\}}{\sum_{m=1}^M \exp\{-y_{(m)}\}}. \quad (1.5)$$

The $M \times N$ latents \mathcal{Y} add many degrees of freedom to the model, enormously expanding the parameter space. A proper prior ($a, b > 0$) for $\sigma_{(m)}^2$ is required to ensure a proper posterior for all N . There is little benefit to allowing a linear mean function, so it is typical to take $f(x) = 0$, and thus $p = 0$, eliminating $\beta_{(m)}$ from the model. Conditional on the $Y_{(m)}$, samples from the posterior of the parameters to the m th GP may be obtained as described above via (1.1). Given parameters, several schemes may be used to sample \mathcal{Y} via (1.3)–(1.4) (see Section 2.2). The predictive distribution, required for our SMC/PL algorithm, is more involved (also deferred to Section 2.2). Almost irrespective of the details of implementation, inference for GP classification is much harder than regression. In practice, only $N \times (M - 1)$ latents, and thus $M - 1$ GPs, are necessary since we may fix $Y_{(M)} = 0$, say, without loss of generality. Although having fewer latents makes inference a little easier, it introduces an arbitrary asymmetry in the prior which may be undesirable. To simplify notation we shall use M throughout, although in our implementations we use $M - 1$.

1.2 SEQUENTIAL MONTE CARLO

Sequential Monte Carlo (SMC) is an alternative to MCMC that is designed for on-line inference in dynamic models. In SMC, *particles* $\{S_t^{(i)}\}_{i=1}^N$ containing the *sufficient information* about all uncertainties given data $z^t = (z_1, \dots, z_t)$ up to time t are used to approximate the posterior distribution: $\{S_t^{(i)}\}_{i=1}^N \sim p(S_t|z^t)$. In Section 2 we describe the sufficient information S_t for our GP regression and classification models. The key task in SMC inference is to *update* the particle approximation from time t to time $t + 1$.

Our preferred SMC updating method is *particle learning* (PL, e.g., [Carvalho et al. 2010](#)) due to the convenient form of the posterior predictive distribution of GP models. The PL update is derived from the following decomposition:

$$\begin{aligned} p(S_{t+1}|z^{t+1}) &= \int p(S_{t+1}|S_t, z_{t+1}) d\mathbb{P}(S_t|z^{t+1}) \\ &\propto \int p(S_{t+1}|S_t, z_{t+1}) p(z_{t+1}|S_t) d\mathbb{P}(S_t|z^t). \end{aligned}$$

This suggests a two-step update of the particle approximation:

1. *resample* the indices $\{i\}_{i=1}^N$ with replacement from a multinomial distribution where each index has weight $w_i \propto p(z_{t+1}|S_t^{(i)}) = \int p(z_{t+1}|S_{t+1}) p(S_{t+1}|S_t) dS_{t+1}$, thus obtaining new indices $\{\zeta(i)\}_{i=1}^N$,
2. *propagate* with a draw from $S_{t+1}^{(i)} \sim p(S_{t+1}|S_t^{\zeta(i)}, z_{t+1})$ to obtain a new collection of particles $\{S_{t+1}^{(i)}\}_{i=1}^N \sim p(S_{t+1}|z^{t+1})$.

The core components of PL are not new to the SMC arsenal. Early examples of related propagation methods include those of [Kong, Liu, and Wong \(1994\)](#), with resampling and the propagation of sufficient statistics by [Liu and Chen \(1995, 1998\)](#), and look-ahead by [Pitt and Shephard \(1999\)](#). Like many SMC algorithms, PL is susceptible to an accumulation of Monte Carlo error with large datasets. However, two aspects of our setup mitigate these concerns to a large extent. First, the overarching goal of sequential design is to keep

datasets as small as possible. GPs scale poorly to large datasets anyways, regardless of the method of inference (SMC, MCMC, etc.), so drastically different approaches are recommended for large-scale sequential design. Second, we only use vague priors for parameters which can be analytically integrated out in the posterior predictive—the main workhorse of PL—so that there is no need to sample them. In this way we extend the class of models for which SMC algorithms apply. However, we note that in order to use vague priors we must initialize the particles at some time $t_0 > 0$. Further explanation and development is provided in Section 2.

2. PARTICLE LEARNING FOR GAUSSIAN PROCESSES

To implement PL for GPs we need to: identify the sufficient information S_t ; initialize the particles; derive $p(z_{t+1}|S_t)$ for the resample step; and determine $p(S_{t+1}|S_t, z_{t+1})$ for the propagate step. We first develop these quantities for GP regression and then extend them to classification. Although GPs are not dynamic models, we will continue to index the data size, which was N in D_N in Section 1.1, with t in the SMC framework so that $z^t \equiv D_N$. We use N for the number of particles. As GPs are nonparametric priors, their sufficient information has size in $\Omega(t)$, that is, they depend upon the full z^t . For example, the covariance $\Sigma(X_t)$ typically requires maintaining $O(t^2)$ quantities to store the distances between the pairs of rows in X_t . Therefore z^t is tacitly part of the sufficient information S_t .

2.1 REGRESSION

Sufficient Information

Recall that $z_t = (X_t, Y_t)$ in the regression setup. From our discussion in Section 1.1, the sufficient information, S_t , needed for GP regression comprises only the parameters of $K(\cdot, \cdot)$, defining K_t via the pairs of rows in X_t . All of the other necessary quantities ($\tilde{\beta}_t \equiv \tilde{\beta}(K_t)$ and $\psi_t \equiv \psi(K_t)$) may be calculated directly from K_t and z^t . However, we prefer to think of the sufficient information as $S_t = \{K_t, \tilde{\beta}_t, \psi_t\}$ for a clearer presentation and efficient implementation.

Initialization

Particle initialization depends upon the choice of prior for σ^2 . With a proper prior ($a, b > 0$) we may initialize the N particles at time $t_0 = 0$ with a sample of the $K(\cdot, \cdot)$ parameterization from its prior, $K_0^{(i)} \stackrel{\text{iid}}{\sim} \pi(K)$. We then calculate $\tilde{\beta}_0^{(i)}, \psi_0^{(i)}$ from $K_0^{(i)}$ following (1.2), thereby obtaining $S_0^{(i)}$. To take an improper prior ($a, b = 0$) on σ^2 requires initializing the particles conditional upon $t_0 > p + 1$ data points to ensure a proper posterior. In other words, we must start the SMC algorithm at a time later than zero. We find that a MH scheme for obtaining $K_{t_0}^{(i)} \sim p(K|z^{t_0})$, via proposals from the prior $\pi(K)$ and accepting via (1.1), works well for t_0 small (i.e., not much larger than $p + 1$) since the prior is similar to the posterior ($p(K|z^{t_0})$) in this case. We may then calculate $\tilde{\beta}_{t_0}^{(i)}, \psi_{t_0}^{(i)}$ from $K_{t_0}^{(i)}$ and z^{t_0} following (1.2), thereby obtaining $S_{t_0}^{(i)}$. Both approaches (proper or improper

prior for σ^2) require a proper prior on the parameters to $K(\cdot, \cdot)$. Sensible defaults exist for many of the typical choices for $K(\cdot, \cdot)$. One such choice is suggested in our illustration, to follow shortly.

Resample

Technically, calculating the weights for the resample step requires integrating over $p(S_{t+1}|S_t)$. But since the GP is not a dynamic model we can only talk about S_{t+1} conditional on $z_{t+1} = (x_{t+1}, y_{t+1})$. Therefore, $p(z_{t+1}|S_t^{(i)})$ is just the probability of y_{t+1} under the Student- t (1.3)–(1.4) given $S_t^{(i)}: w_t^{(i)} \propto p(y(x_{t+1})|z^t, K_t^{(i)}) \equiv p(y(x_{t+1})|z^t, K_t^{(i)}, \tilde{\beta}_t^{(i)}, \psi_t^{(i)})$.

Propagate

The propagate step updates each resampled sufficient information $S_t^{\zeta(i)}$ to account for $z_{t+1} = (x_{t+1}, y_{t+1})$. Since the parameters to $K(\cdot, \cdot)$ are static, that is, they do not change in t , they may be propagated deterministically by copying them from $S_t^{\zeta(i)}$ to $S_{t+1}^{(i)}$. We note that, as a matter of efficient bookkeeping, it is the correlation matrix K_{t+1} and its inverse K_{t+1}^{-1} that are required for our PL update, not the values of the parameters directly. The new $K_{t+1}^{(i)}$ is built from $K_t^{(i)}$ and $K^{(i)}(x_{t+1}, x_j)$, for $j = 1, \dots, t+1$, as

$$K_{t+1}^{(i)} = \begin{bmatrix} K_t^{(i)} & k_t^{(i)}(x_{t+1}) \\ k_t^{(i)\top}(x_{t+1}) & K^{(i)}(x_{t+1}, x_{t+1}) \end{bmatrix}.$$

The partition inverse equations yield $(K_{t+1}^{(i)})^{-1}$ in $O(t^2)$ rather than $O(t^3)$:

$$(K_{t+1}^{(i)})^{-1} = \begin{bmatrix} [(K_t^{(i)})^{-1} + g_t^{(i)}(x_{t+1})g_t^{(i)\top}(x_{t+1})/\mu_t^{(i)}(x_{t+1})] & g_t^{(i)}(x_{t+1}) \\ g_t^{(i)\top}(x_{t+1}) & \mu_t^{(i)}(x_{t+1}) \end{bmatrix},$$

where $g(x) = -\mu(x)K^{-1}k(x)$ and $\mu(x) = [K(x, x) - k^\top(x)K^{-1}k(x)]^{-1}$. Using (1.2) to calculate $\tilde{\beta}_{t+1}^{(i)}(K_{t+1}^{(i)})$ and $\psi_{t+1}^{(i)}(K_{t+1}^{(i)})$ takes time in $O(t^2)$. It is possible to update these quantities in $O(\max\{t, p\})$ time (e.g., Escobar and Moser 1993) from their counterparts in $S_t^{\zeta(i)}$ and the new z_{t+1} . However, this would not improve upon the overall complexity of the propagate step so we prefer the simpler expressions (1.2).

Deterministically copying $K(\cdot, \cdot)$ in the propagate step is fast, but it may lead to particle depletion in future resample steps. An alternative is to augment the propagate with a sample from the posterior distribution via MCMC to *rejuvenate* the particles (e.g., MacEachern, Clyde, and Liu 1999; Gilks and Berzuini 2001). In our regression GP context, just a single MH step for the parameters to $K(\cdot, \cdot)$ using (1.1), for each particle, suffices. The particles represent “chains” in equilibrium so it is sensible to tune the MH proposals for likely acceptance by making their variance small, initially, relative to the posterior at the starting time $t = t_0$, and then further decreasing it multiplicatively as t increments. Such MH rejuvenations position the propagate step as a local maneuver in the Monte Carlo method, whereas resampling via the predictive is a more global step. Together they can emulate an ensemble method.

An Illustration

In our illustrations we follow [Gramacy and Lee \(2008\)](#) and take $K(\cdot, \cdot)$ to have the form $K(x, x'|g) = K^*(x, x') + g\delta_{x, x'}$, where $\delta_{\cdot, \cdot}$ is the Kronecker delta function, and $-1 \leq K^*(x, x') \leq 1$. The g term, referred to as the *nugget*, must be positive and provides a mechanism for introducing measurement error into the stochastic process. It causes the predictive equations (1.3)–(1.4) to smooth rather than interpolate, encoding ([Gramacy 2005](#), appendix B) the process $Y(x) = \mu(x) + \varepsilon(x) + \eta$, where μ is the mean, ε is the GP covariance structure ($\sigma^2 K^*(\cdot, \cdot)$), and η is the noise process ($\sigma^2 g$). We take $K^*(\cdot, \cdot)$ to be an isotropic Gaussian correlation function with unknown *range* parameter d : $K^*(x, x'|d) = \exp\{\|x - x'\|^2/d\}$. Upon scaling the inputs (X) to lie in $[0, 1]^p$ and the outputs (Y) to have a mean of zero and a range of 1, it is easy to design priors for d and g since the range of plausible values is greatly restricted. We use $\text{Exp}(\lambda = 5)$ for both parameters throughout. Random-walk MH proposals from a uniform “positive sliding window” centered around the previous setting work well for both parameters. For example, $d^* \sim \text{Unif}(\ell d/u, ud/\ell)$ for $u > \ell > 0$. The setting $(u, \ell) = (4, 3)$ is a good baseline ([Gramacy 2007](#)). When using MH for rejuvenation one may increase u and ℓ with t to narrow the locality.

Consider the 1-dimensional synthetic sinusoidal data first used by [Higdon \(2002\)](#),

$$y(x) = \sin\left(\frac{\pi x}{5}\right) + \frac{1}{5} \cos\left(\frac{4\pi x}{5}\right), \quad (2.1)$$

where $x \in [0, 9.6]$, capturing two periods of low-fidelity oscillation (the sine term). We observe the response with noise $Y(x) \sim N(y(x), \sigma = 0.1)$. At this noise level it is difficult to distinguish the high-fidelity oscillations (the cosine term) from the noise without many samples. We used a $T = 50$ Latin hypercube design (LHD, e.g., [Santner, Williams, and Notz 2003](#), sec. 5.2.2)—just large enough to begin to detect the high-fidelity structure.

For PL we used $N = 1000$ particles with an improper, scale-invariant prior ($a, b = 0$) for σ^2 . The particles were initialized at time $t_0 = 5$ via 10,000 MH rounds, saving every 10th. This took about 30 seconds in our R implementation on a 3 GHz Athalon workstation. The remaining 45 PL updates with MH rejuvenation steps ($O(t^3)$) following deterministic propagates took about 5 minutes: the first few ($t < 10$) took seconds, whereas the last few ($t > 45$) took tens of seconds. It is this fast between-round updating that we exploit for sequential design in Section 3. Foregoing rejuvenation ($O(t^2)$) drastically reduces the computational demands for fixed N , but larger N is needed to get a good fit due to particle depletion.

The left panel of Figure 1 shows the pointwise predictive distribution for each of the 1000 particles in terms of the mean(s) and central 90% credible interval(s) of the Student- t distributions (1.3)–(1.4) with parameters $\hat{y}_t^{(i)}$, $\hat{\sigma}_t^{2(i)}$, and $\hat{v}_t^{(i)}$ obtained from $S_t^{(i)}$. Their average, the posterior mean predictive surface, is shown on the right. Observe that some particles lead to higher fidelity surfaces (finding the cosine) than others (only finding the sine). Figure 2 shows the samples of the range (d) and nugget (g) obtained from the particles. Only 200 of the 1000 are shown to reduce clutter. The clustering pattern of the black diamonds indicates a multimodal posterior.

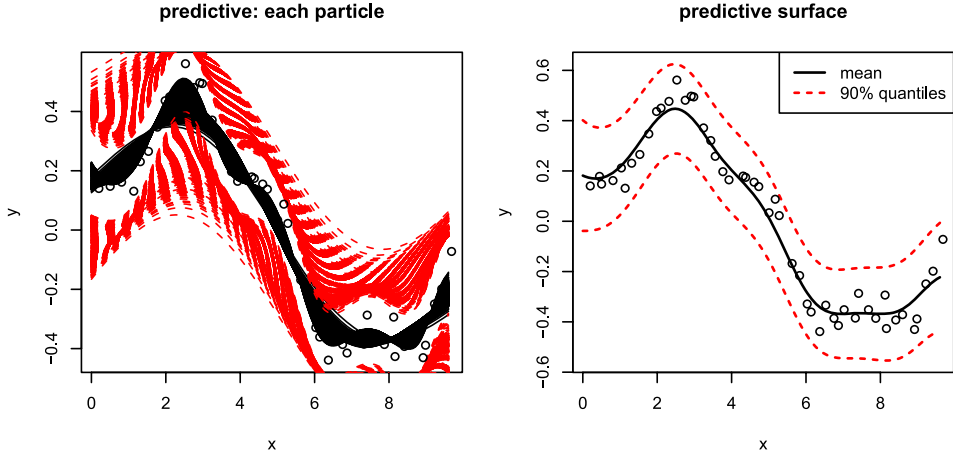


Figure 1. Predictive surface(s) for the sinusoidal data in terms of the posterior mean (black solid) and central 90% credible interval(s) (red dashed). Each particle is represented on the left with three lines, and the average of the particles is on the right. The online version of this figure is in color.

For contrast we also took 10,000 MCMC samples from the full data posterior, thinning every 10 and saving 1000. This took about 1 minute on our workstation, which is faster than the full PL run, but much slower than the individual updates $t \rightarrow t + 1$. The marginal chains for d and g seemed to mix well (not shown) but, as Figure 2 shows (plotting last 200 sample pairs as red squares), the chain nevertheless became stuck in a mode of the posterior, and only explored a portion of the high-density region.

For a more numerical comparison we calculated the RMSE of predictive means (obtained via PL and MCMC, as above) to the truth on a random LHD of size 1000. This was repeated 100 times, each with new LHD training (size 50, as above) and test sets. The mean

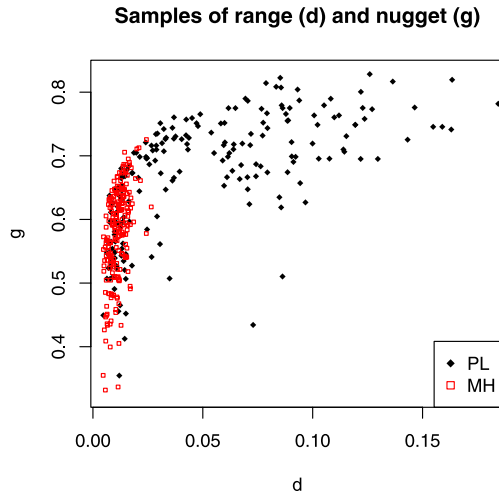


Figure 2. 200 samples of the range (d) and nugget (g) parameter obtained from particles (black diamonds) and from MCMC (red squares). The online version of this figure is in color.

(sd) RMSE was 0.00079 (0.00069) for PL, and 0.00098 (0.00075) for MCMC. As paired data, the average number of times PL had a lower RMSE than MCMC was 0.64, which is statistically significant ($p = 5.837 \times 10^{-5}$) using a standard one-sided t -test. In short, this means that the SMC/PL method is performing at least as well as the MCMC with quicker sequential updates. The MCMC could be retuned, restarted, and/or run for longer to narrow the RMSE gap, but all of these would come at greater computational expense.

2.2 CLASSIFICATION

Sufficient Information

In classification we use M GP priors on $M \times t$ latent variables. Therefore, S_t comprises $\{K_{(m),t}, \tilde{\beta}_{(m),t}, \psi_{(m),t}\}_{m=1}^M$ and \mathcal{Y}^t .

Initialization

Particle initialization is identical to an M -fold application of regression GP particle initialization. As remarked in Section 1.1, we must use a proper prior ($a, b > 0$) for each $\sigma_{(m)}^2$. As a consequence, we may initialize all of the particles at $t_0 = 0$ by sampling $\{K_{(m),0}^{(i)}\}_{m=1}^M$ identically from $\pi(K)$. There are no latent \mathcal{Y} at time zero, so neither they nor $\{\tilde{\beta}_{(m),0}, \psi_{(m),0}\}_{m=1}^M$ are required. It is also possible to initialize the particles at $t_0 > 0$, which may be desirable in some situations. In this case, a hybrid of the MH scheme for regression GPs, applied M -fold, and a sampling of the latent \mathcal{Y}^{t_0} yielding $\{\tilde{\beta}_{(m),t_0}, \psi_{(m),t_0}\}_{m=1}^M$, as described below for the propagate step, works well.

Resample

It may be helpful to think of the latent \mathcal{Y}^t as playing the role of (hidden) states in a dynamic model. Indeed, their treatment in the PL update is similar. However, note that they do not satisfy any Markov property. The predictive density $p(z_{t+1}|S_t)$, which is needed for the resample step, is the probability of the label $c_{t+1}(x_{t+1})$ under the sufficient information S_t : $p(c_{t+1}(x_{t+1})|S_t)$. This depends upon the M latents $\mathcal{Y}(x_{t+1})$, which are not part of S_t . For an arbitrary x , the law of total probability gives

$$\begin{aligned} p(c(x)|S_t) &= \int_{\mathbb{R}^M} p(c(x), \mathcal{Y}(x)|S_t) d\mathcal{Y}(x) \\ &= \int_{\mathbb{R}^M} p(c(x)|\mathcal{Y}(x)) p(\mathcal{Y}(x)|S_t) d\mathcal{Y}(x). \end{aligned} \quad (2.2)$$

The second equality comes since, conditional on $\mathcal{Y}(x)$, the label does not depend on any other quantity (1.5). The M GP priors are independent, so $p(\mathcal{Y}(x)|S_t)$ decomposes as

$$p(\mathcal{Y}(x)|S_t) = \prod_{m=1}^M p(y_{(m)}(x)|Y_{(m),t}, K_{(m),t}), \quad (2.3)$$

where each component in the product is a Student- t density (1.3)–(1.4).

The M -dimensional integral in (2.2) is not analytically tractable, but it is trivial to approximate by Monte Carlo as follows. Simulate many independent collections of samples from each of the M Student- t distributions (2.3):

$$\tilde{Y}(x)^{(\ell)} = \{\tilde{y}_{(m)}(x)^\ell\}_{i=1}^M, \quad \text{where } \tilde{y}_{(m)}(x)^\ell \stackrel{\text{iid}}{\sim} p(y_{(m)}(x) | Y_{(m),t}, K_{(m),t}) \quad (2.4)$$

for $\ell = 1, \dots, L$, say—thereby collecting $M \times L$ samples. Then pass these latents through the likelihood (1.5) and take an average:

$$p(c(x) | S_t) \approx \frac{1}{L} \sum_{\ell=1}^L p(c(x) | \tilde{Y}(x)^{(\ell)}). \quad (2.5)$$

With as few as $L = 100$ samples this approximation is quite accurate. The weights $\{w_i\}_{i=1}^N$, where $w_i \propto p(c_{t+1}(x_{t+1}) | S_t^{(i)})$, may be used to obtain the resampled indices $\{\zeta(i)\}_{i=1}^N$. Observe that even $L = 1$ is possible, since we may then view $\tilde{Y}(x)^{(1)}$ as an auxiliary member of the state S_t . So any inaccuracies in the approximation simply contribute to the Monte Carlo error of the PL method, which may be squashed with larger N .

Propagate

The GP classification propagate step is essentially the aggregate of M regression propagates. But these may only commence once the new latent(s) for $t + 1$ are incorporated. We may extend the hidden state analogy to sample $\mathcal{Y}_{t+1}^{\zeta(i)} \sim p(\mathcal{Y}(x_{t+1}) | S_t^{\zeta(i)})$ via the independent Student- t distributions (2.3). In expectation we have that $\{\tilde{\beta}_{(m),t}^{\zeta(i)}, \psi_{(m),t}^{\zeta(i)}\}_{m=1}^M = \{\tilde{\beta}_{(m),t}^{\zeta(i)}, \psi_{(m),t}^{\zeta(i)}\}_{m=1}^M | \mathcal{Y}^{t+1,\zeta(i)}, \{K_{(m),t}^{\zeta(i)}\}_{m=1}^M$ since $\mathcal{Y}_{t+1}^{\zeta(i)} \sim p(\mathcal{Y}(x_{t+1}) | S_t^{\zeta(i)})$, so no update of the rest of the sufficient information is necessary at this juncture. To complete the propagation we must sample the full set of latents $\mathcal{Y}^{t+1,\zeta(i)}$ conditional upon c_{t+1} via z^{t+1} . Once obtained, these fully propagated latents $\mathcal{Y}^{t+1,(i)}$ may be used to update the remaining components of the sufficient information: $\{\tilde{\beta}_{(m),t+1}^{(i)}, \psi_{(m),t+1}^{(i)}, K_{(m),t+1}^{(i)}\}_{m=1}^M | \mathcal{Y}^{t+1,(i)}$ comprising $S_{t+1}^{(i)}$.

Sampling the latents may proceed via ARS, following Neal (1998). However, as in the regression setup, we prefer a more local move in the PL propagate context to complement the globally scoped resample step. So instead we follow Broderick and Gramacy (2010) in using 10-fold randomly blocked MH-within-Gibbs sampling. This approach exploits a factorization of the posterior as the product of the class likelihood (1.5) given the underlying latents and their GP prior (2.2) (dropping the $\zeta(i)$):

$$p(C(X_I) | \mathcal{Y}^{t+1}(X_I)) \times p(Y_{(m)}^{t+1}(X_I) | Y_{(m)}^{t+1}(X_{-I}), K(\cdot, \cdot)). \quad (2.6)$$

Here, I is an element of a 10-fold (random) partition \mathcal{I}_{10} of the indices $1, \dots, t + 1$, where $|I| \leq 10$ and $-I = \mathcal{I}_{10} \setminus I$ is its complement. Extending the predictive equations from Section 2.1, the latter term in (2.6) is an $|I|$ -dimensional Student- t with $\hat{v}_I = |-I| - p - 1$,

$$\text{mean vector: } \hat{Y}_I = F_I \tilde{\beta}_{-I} + K_{I,-I}, K_{-I,-I}^{-1} (Y_{-I} - F_{-I} \tilde{\beta}_{-I})$$

and

$$\text{scale matrix: } \hat{\Sigma}_{I,I} = \frac{(b + \psi_{-I})[K_{I,-I} - K_{I,-I} K_{I,I}^{-1} K_{-I,I}]}{a + \hat{v}_I},$$

using the condensed notation $Y_I \equiv Y_{(m)}(X_I)$, and $|I| \times |I'|$ matrix $K_{I,I'} \equiv K_{(m)}(X_I, X_{I'})$, etc. A thus proposed $Y'_{(m)}(X_I)$ may be accepted according to the likelihood ratio since the prior and proposal densities cancel in the MH acceptance ratio. Let \mathcal{Y}'_I denote the collection of $M \times (t + 1)$ latents composed of $Y'_{(m)}(X_I)$, $Y_{(-m)}^{t+1}(X_I)$, and $\mathcal{Y}^{t+1}(X_{-I})$. Then the MH acceptance probability is $\min\{1, A\}$ where

$$A = \frac{p(C(X_I)|\mathcal{Y}'_I)}{p(C(X_I)|\mathcal{Y}_I^{t+1})} = \prod_{i \in I} \frac{p(c_i|\mathcal{Y}'_i)}{p(c_i|\mathcal{Y}_i^{t+1})}.$$

Upon acceptance we replace $Y_{(m)}^{t+1}(X_I)$ with $Y'_{(m)}(X_I)$, and otherwise do nothing. In this way we loop over $m = 1, \dots, M$ and $I \in \mathcal{I}_{10}$ to obtain a set of fully propagated latents.

An Illustration

Consider data generated by converting a real-valued output $y(x) = x_1 \exp(-x_1^2 - x_2^2)$ into classification labels (Broderick and Gramacy 2010) by taking the sign of the sum of the eigenvalues of the Hessian of $y(x)$. This gives a two-class process where the class is determined by the direction of concavity at x . For our illustration we take $x \in [-2, 2]^2$, and create a third class from the first class (negative sign) where $x_1 > 0$. We use $M - 1 = 2$ GPs, and take our dataset to be $T = 125$ input-class pairs from a maximum entropy design (MED, Santner, Williams, and Notz 2003, sec. 6.2.1). Our $N = 1000$ particles are initialized using 10,000 MCMC rounds at time $t_0 = 17$, thinning every 10. This takes less than 2 minutes in R on our workstation. Then we proceed with 108 PL updates, which takes about 4 hours. The first few updates take less than a minute, whereas the last few take 7–8 minutes.

Figure 3 shows the posterior predictive surface, interpolated from 1000 MED test locations, in terms of the most likely label from the mean posterior predictive (left), that is, $\arg \max_m N^{-1} \sum_{i=1}^N p_m^{(i)}(x)$ where $p_m^{(i)}(x) \equiv p(c(x) = m)^{(i)} \approx p(C(x) = m | \mathcal{S}_t^{(i)})$, and the mean entropy (right) of the label distribution $-\sum_{m=1}^M p_m^{(i)}(x) \log p_m^{(i)}(x)$. The 125 training inputs are shown as open black circles and the 76 misclassified test locations are shown as solid red ones. Observe that the predictive entropy is highest where determining the class label is most difficult: near the boundaries.

The differences in Monte Carlo efficiency between PL and MCMC, here, are less stark. There is less scope for the posterior to be multimodal due to the role of the nugget. For classification, the nugget parameterizes the continuum between logit (small nugget) and probit (large nugget) models (Neal 1998), which is far more subtle than interpolation versus smoothing as in regression. In terms of computational complexity we can offer the following comparison. Obtaining 10,000 MCMC samples, thinning every 10, for the full $T = 125$ input-class pairs took about 45 minutes. While this is several times faster than PL on aggregate, observe that a single PL update for the 126th input-class pair can be performed several times faster than running a full MCMC from scratch.

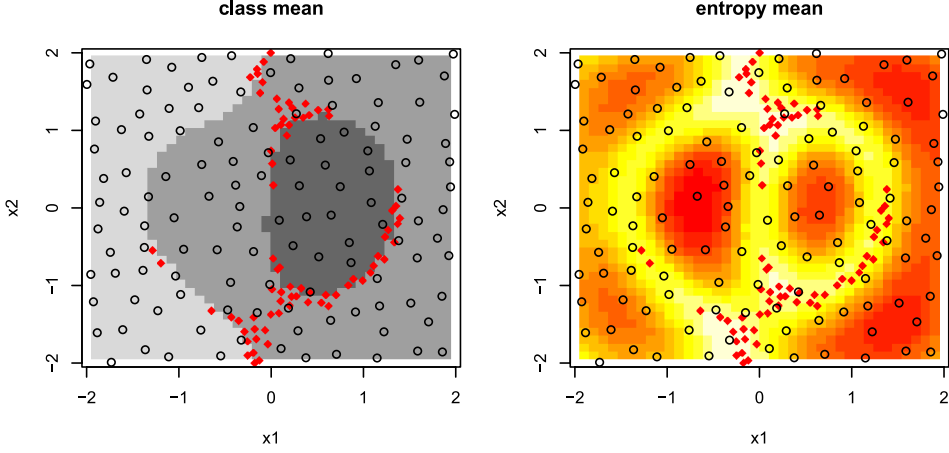


Figure 3. Class posterior mean (left) and entropy posterior mean (right) for the PL fit to the three-class 2-d exponential data. The classes are represented by three shades of gray; and the heat map for the entropy is hottest (whitest) for large values. The inputs are black open circles, and the misclassified predictive locations are solid red circles. The online version of this figure is in color.

For a further comparison of timings on a larger classification problem we duplicated the 10-fold cross-validation (CV) experiment of [Broderick and Gramacy \(2010\)](#) on the two-class credit approval data which has $p = 47$ covariates for 690 (x, c) pairs. The time required for the final PL update ($t \approx 621$) with $N = 1000$ particles, averaged over the 10 CV folds, was 38 minutes. The resulting predictor(s) gave exactly the same misclassification error(s) averaging 14.6% (4% sd) on the hold-out sets as a similar estimator based on MCMC. However, the authors reported that the MCMC took about 5.5 hours on average. So even with a modestly large design (≈ 621), the Monte Carlo error that might accumulate with the use of vague priors in SMC does not seem to (yet) be an issue in our PL implementation. The savings in time is huge due to the decomposition of far fewer 621×621 covariance matrices in the SMC framework.

3. SEQUENTIAL DESIGN

Here, we illustrate how the online nature of PL is ideally suited to sequential design by AL. Probably the most straightforward AL algorithms in the regression context are ALM and ALC (see Section 1.1). But these are well known to approximate space-filling MEDs for stationary GP models. So instead we consider the sequential design problem of optimizing a noisy black box function. In the classification context we consider the sequential exploration of classification boundaries.

3.1 OPTIMIZATION BY EXPECTED IMPROVEMENT

[Jones, Schonlau, and Welch \(1998\)](#) described how to optimize a deterministic black box function using a “surrogate” model (i.e., a GP with $g = 0$) via the MLE (for $\{d, \beta, \sigma^2\}$). The essence is as follows. After t samples are gathered, the current minimum is $f_{\min,t} =$

$\min\{y_1, \dots, y_t\}$. The improvement at x is $I_t(x) = \max\{f_{\min,t} - Y_t(x), 0\}$, a random variable whose distribution is determined via $Y_t(x) \equiv Y(x)|z^t, K_t$, which has a Student- t distribution (1.3)–(1.4). The *expected improvement* (EI) is obtained by analytically integrating out $Y_t(x)$. A branch-and-bound algorithm is then used to maximize the EI to obtain the next design point $x_{t+1} = \arg \max \mathbb{E}\{I_t(x)\}$. The resulting iterative procedure (choose x_{t+1} ; obtain $y_{t+1}(x_{t+1})$; refit and repeat) is called the *efficient global optimization* (EGO) algorithm.

The situation is more complicated when optimizing a noisy function, or with Bayesian inference via Monte Carlo. A redefinition of $f_{\min,t}$ accounts for the noisy ($g > 0$) responses: either as the first-order statistic of $Y(X_t)$ or as the minimum of the predictive mean surface, $\min_x \hat{y}_t(x)$. Now, each sample (e.g., each particle) from the posterior emits an EI. Using our Student- t predictive equations (1.3)–(1.4) for $S_t^{(i)}$, letting $\delta_t^{(i)}(x) = f_{\min,t} - \hat{y}_t^{(i)}(x)$, we have (following Williams et al. 2000):

$$\begin{aligned} \mathbb{E}\{I_t(x)|S_t^{(i)}\} &= \delta_t^{(i)}(x) T_{\hat{v}_t^{(i)}}\left(\frac{\delta_t^{(i)}(x)}{\hat{\sigma}_t^{(i)}(x)}\right) \\ &+ \frac{1}{\hat{v}_t^{(i)} - 1} \left[\hat{v}_t^{(i)} \hat{\sigma}_t^{(i)}(x) + \frac{\delta_t^{(i)}(x)^2}{\hat{\sigma}_t^{(i)}(x)} \right] t_{\hat{v}_t^{(i)}}\left(\frac{\delta_t^{(i)}(x)}{\hat{\sigma}_t^{(i)}(x)}\right). \end{aligned} \quad (3.1)$$

The EI is then approximated as $\mathbb{E}\{I_t(x)\} \approx N^{-1} \sum_{i=1}^N \mathbb{E}\{I_t(x)|S_t^{(i)}\}$, thereby taking parameter uncertainty into account. But the branch-and-bound algorithm no longer applies.

A remedy, proposed to ensure convergence in the optimization, involves pairing EI with a deterministic numerical optimizer. Taddy et al. (2009) proposed using a GP/EI-based approach (with MCMC) as an oracle in a pattern search optimizer called APPS. This high-powered combination offers convergence guarantees, but unfortunately requires a highly customized implementation that precludes its use in our illustrations. Gramacy and Taddy (2010, sec. 3) proposed a simpler, more widely applicable, variant via the opposite embedding. There are (as yet) no convergence guarantees for this heuristic, but it has been shown to perform well in many examples.

Both methods work with a fresh set of random candidate locations \tilde{X}_t at each time t , for example, a LHD. In the oracle approach, the candidate which gives the largest EI, $x_t^* = \arg \max_{\tilde{x} \in \tilde{X}_t} \mathbb{E}\{I_t(\tilde{x})\}$, is used to augment the search pattern used by the direct optimizer (APPS) to find x_{t+1} . In the simpler heuristic approach, the candidate design is augmented to include the minimum mean predictive location based upon the MAP parameterization at time t . In our SMC/PL implementation this involves first finding $i^* = \arg \max_{i=1, \dots, N} p(S_t^{(i)}|z^t)$, and then finding $x_t^* = \arg \min_x \hat{y}_t^{(i^*)}(x)$. (R's `optim` function works well for the latter search when initialized with $\arg \min_{x \in \tilde{X}_t} \hat{y}_t^{(i^*)}(x)$.) We may then take $x_{t+1} = \arg \max_{\tilde{x} \in \tilde{X}_t \cup x_t^*} \mathbb{E}\{I_t(\tilde{x})\}$, having searched both globally via \tilde{X}_t , and locally via x_t^* .

Figure 4 illustrates the progress of this algorithm with PL inference on the 2-d exponential data (Section 2.2), observed with $N(0, \sigma = 0.001)$ noise. The $N = 1000$ particles were initialized at time $t_0 = 7$ with a LHD. Each \tilde{X}_t is a fresh size 40 LHD. The left panel tracks $x_t^* = (x_{1,t}^*, x_{2,t}^*)$, the optimal additional candidate, as lines and the chosen $x_{t+1} = (x_{1,t+1}, x_{2,t+1})$ as points, both from $t = t_0, \dots, T = 50$. Observe how the

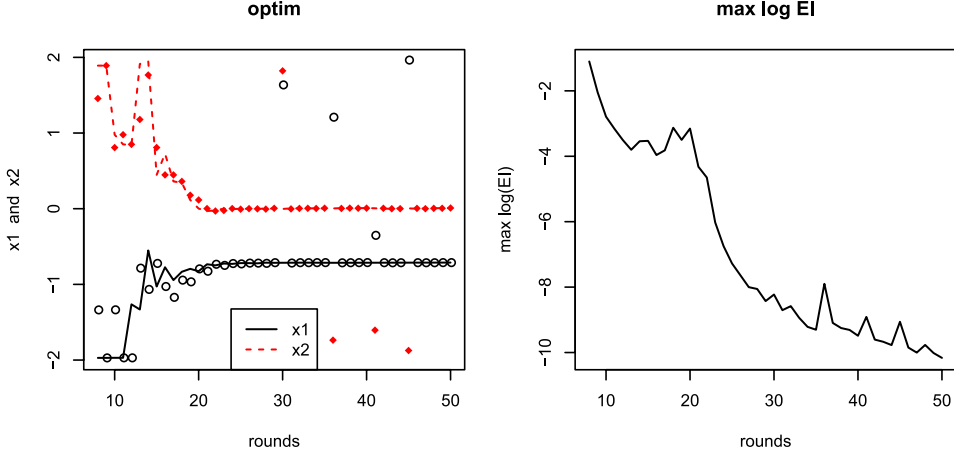


Figure 4. Tracking the progress of GP/EI optimization via PL. The left plot shows x_t (points) and x_t^* (lines); the right plot shows $\log \mathbb{E}\{I_t(x_{t+1})\}$. The online version of this figure is in color.

points initially explore to find a (local) optimum, and then later make excursions (unsuccessfully) in search of an alternative. The right panel tracks the maximum of the log EI, $\log(\mathbb{E}\{I_t(x_{t+1})\})$, from $t = t_0, \dots, T$. Observe that this is decreasing except when $x_{t+1} \neq x_t^*$, corresponding to an exploration event. The magnitude and frequency of these up-spikes decrease over time, giving a good empirical diagnostic of convergence. At the end we obtained $x_T^* = (-0.7119, 0.0070)$, which is very close to the true minimum $x^* = (-\sqrt{1/2}, 0)$. The 43 PL updates, with searches, etc., took about 11 minutes in R on our workstation. By way of comparison, the equivalent MCMC-based implementation (giving nearly identical results) took more than 45 minutes.

3.2 ONLINE LEARNING OF CLASSIFICATION BOUNDARIES

In Section 2.2 (Figure 3) we saw how the predictive entropy could be useful as an AL heuristic for boundary exploration. Joshi, Porikli, and Papanikolopoulos (2009) observed that when $M > 2$, the probability of the irrelevant class(es) near the boundary between two classes can influence the entropy, and thus the sequential design based upon it, in undesirable ways. They showed that restricting the entropy calculation to the two highest probabilities [*best-versus-second-best* (BVSB) entropy] is a better heuristic.

Figure 5 shows the sequential design obtained via PL with $N = 1000$ particles and the BVSP entropy AL heuristic using a predefined set of 300 MED candidate locations. The design was initialized with a $t_0 = 25$ sub-MED (from the 300), and AL was performed at each of rounds $t = t_0, \dots, T = 125$ on the $300 - t$ remaining candidates. This time there are 40 misclassified points, compared to the 76 obtained with a static design (Section 2.2; the same 1000 MED test set was used). The running time here is comparable to the static implementation. MCMC gives similar results but takes 4–5 times longer.

Working off-grid, for example, with a fresh set of LHD candidates in each AL round, is slightly more challenging because the predictive entropy is very greedy. Paradoxically, the highest (BVSB) entropy regions tend to be near the boundaries which have been most

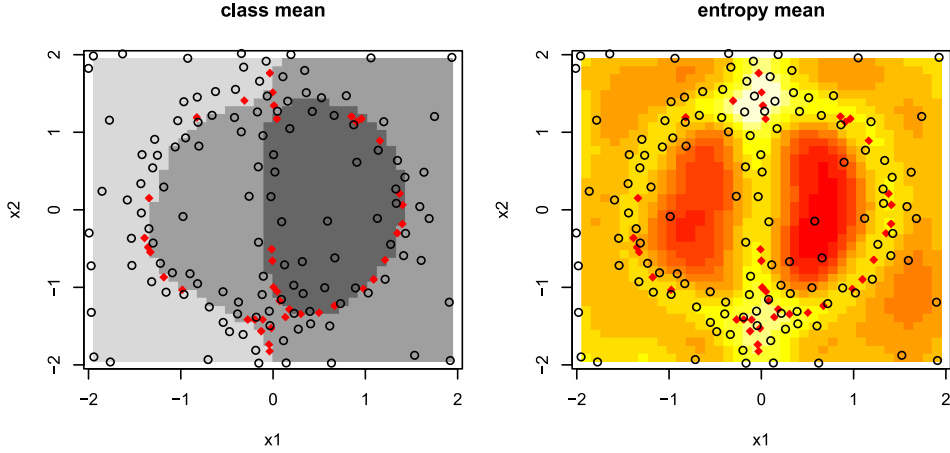


Figure 5. Class posterior mean (left) and entropy posterior mean (right) for the PL fit to the three-class 2-d exponential data by AL with the BVS entropy heuristic, for comparison with the static design version in Figure 3. The online version of this figure is in color.

thoroughly explored—straddling them with a high concentration of points—even though the entropy rapidly decreases nearby. One possible remedy involves smoothing the entropy by a distance-based kernel (e.g., $K(\cdot, \cdot)$ from the GP) over the candidate locations. Applying this heuristic leads to very similar results as those reported in Figure 5, and so they are not shown here.

4. DISCUSSION

We have shown how GP models, for regression and for classification, may be fit via the sequential Monte Carlo (SMC) method of particle learning (PL). We developed the relevant expressions, and provided illustrations on data from both contexts. Although SMC methods are typically applied to time series data, we argued that they are also well suited to scenarios where the data arrive online even when there is no time or dynamic component in the model. Examples include sequential design and optimization, where a significant aspect of the problem is to choose the next input and subsequently update the model fit. In these contexts, MCMC inference has reigned supreme. But MCMC is clearly ill-suited to online data acquisition, as it must be restarted when the new data arrive. We showed that the PL update of a particle approximation is thrifty by contrast, and that adding rejuvenation to the propagate steps mimicks the behavior of an ensemble without explicitly maintaining one.

Another advantage of SMC methods is that they are “embarrassingly parallelizable,” since many of the relevant calculations on the particles may proceed independently of one another, up to having a unique computing node for each particle. In contrast, the Markov property of MCMC requires that the inferential steps, to a large extent, proceed in serial. Getting the most mileage out of our SMC/PL approach will require a careful asynchronous implementation. Observe that the posterior predictive distribution, and the propagate step,

may be calculated for each particle in parallel. Resampling requires that the particles be synchronized, but this is fast once the particle predictive densities have been evaluated. Our implementation in the `plgp` package does not exploit this parallelism. However, it does make heavy use of R's `lapply` method, which automatically loops over the particles to calculate the predictive, and to propagate. A parallelized `lapply`, for example, using `snowfall` and `sfCluster`, as described by Knaus et al. (2009), may be a promising way forward.

SUPPLEMENTARY MATERIALS

R package `plgp`: Our R package `plgp`, version 1.0 from CRAN, contains the core PL framework for GP regression and classification with AL hooks, and each of the synthetic illustrations provided in this article is reworked as “demos” therein. Once the package is installed in the usual way [say using R CMD INSTALL on unix(es)], and loaded in R with `library(plgp)`, a list of demos may be obtained with `demo(package="plgp")`. Alternatively, the help system provides similar pointers via `?plgp`. (`plgp_1.0.tar.gz`, GNU zipped tar file)

ACKNOWLEDGMENTS

This work was partially supported by Engineering and Physical Sciences Research Council grant EP/D06570 4/1 to RBG. We thank four anonymous referees, the associate editor, and editor, whose many helpful comments led to many improvements in the article.

[Received September 2009. Revised July 2010.]

REFERENCES

- Abrahamsen, P. (1997), “A Review of Gaussian Random Fields and Correlation Functions,” Technical Report 917, Norwegian Computing Center, Box 114 Blindern, N-0314 Oslo, Norway. [103]
- Broderick, T., and Gramacy, R. (2010), “Classification and Categorical Inputs With Treed Gaussian Process Models,” technical report, University of Cambridge. Available at *ArXiv:0904.4891*. [111-113]
- Carvalho, C., Johannes, M., Lopes, H., and Polson, N. (2010), “Particle Learning and Smoothing,” *Statistical Science*, 25 (1), 88–106. [105]
- Cohn, D. A. (1996), “Neural Network Exploration Using Optimal Experimental Design,” *Neural Networks*, 9 (6), 1071–1083. [103]
- Escobar, L. A., and Moser, E. B. (1993), “A Note on the Updating of Regression Estimates,” *The American Statistician*, 47 (3), 192–194. [107]
- Gilks, W., and Berzuini, C. (2001), “Following a Moving Target: Monte Carlo Inference for Dynamic Bayesian Models,” *Journal of the Royal Statistical Society, Ser. B*, 63, 127–146. [107]
- Gramacy, R. B. (2005), “Bayesian Treed Gaussian Process Models,” Ph.D. thesis, University of California, Santa Cruz. [104,108]
- (2007), “`tgp`: An R Package for Bayesian Nonstationary, Semiparametric Nonlinear Regression and Design by Treed Gaussian Process Models,” *Journal of Statistical Software*, 19, 9. [108]
- (2010), “`plgp`: Particle Learning of Gaussian Processes,” R package version 1.0. [103]

- Gramacy, R. B., and Lee, H. K. H. (2008), “Bayesian Treed Gaussian Process Models With an Application to Computer Modeling,” *Journal of the American Statistical Association*, 103, 1119–1130. [108]
- (2009), “Adaptive Design and Analysis of Supercomputer Experiment,” *Technometrics*, 51 (2), 130–145. [103]
- Gramacy, R. B., and Taddy, M. A. (2010), “Categorical Inputs, Sensitivity Analysis, Optimization and Importance Tempering With `tgp` Version 2, an R Package for Treed Gaussian Process Models,” *Journal of Statistical Software*, 33 (6). [114]
- Higdon, D. (2002), “Space and Space–Time Modeling Using Process Convolutions,” in *Quantitative Methods for Current Environmental Issues*, eds. C. Anderson, V. Barnett, P. C. Chatwin, and A. H. El-Shaarawi, London: Springer-Verlag, pp. 37–56. [108]
- Jones, D., Schonlau, M., and Welch, W. J. (1998), “Efficient Global Optimization of Expensive Black Box Functions,” *Journal of Global Optimization*, 13, 455–492. [103,113]
- Joshi, A., Porikli, F., and Papanikolopoulos, N. (2009), “Multi-Class Active Learning for Image Classification,” in *Computer Vision and Pattern Recognition, IEEE Computer Society Conference on*, Los Alamitos, CA: IEEE Computer Society, pp. 2372–2379. [103,115]
- Knaus, J., Porzelius, C., Binder, H., and Schwarzer, G. (2009), “Easier Parallel Computing in R With `snowfall` and `sfCluster`,” *The R Journal*, 1 (1), 47–53. [117]
- Kong, A., Liu, J., and Wong, W. (1994), “Sequential Imputations and Bayesian Missing Data Problems,” *Journal of the American Statistical Association*, 89, 278–288. [105]
- Liu, J., and Chen, R. (1995), “Blind Deconvolution via Sequential Imputations,” *Journal of the American Statistical Association*, 90 (430), 567–576. [105]
- (1998), “Sequential Monte Carlo Methods for Dynamic Systems,” *Journal of the American Statistical Association*, 93, 1032–1044. [105]
- MacEachern, S., Clyde, M., and Liu, J. (1999), “Sequential Importance Sampling for Nonparametric Bayes Models: The Next Generation,” *Canadian Journal of Statistics*, 27, 251–267. [107]
- MacKay, D. J. C. (1992), “Information–Based Objective Functions for Active Data Selection,” *Neural Computation*, 4 (4), 589–603. [102]
- Müller, P., Sansó, B., and de Iorio, M. (2004), “Optimal Bayesian Design by Inhomogeneous Markov Chain Simulation,” *Journal of the American Statistical Association*, 99 (467), 788–798. [102]
- Neal, R. M. (1998), “Regression and Classification Using Gaussian Process Priors” (with discussion), in *Bayesian Statistics*, Vol. 6, eds. J. M. Bernardo et al., Oxford, U.K.: Oxford University Press, pp. 476–501. [102,104,111,112]
- Pitt, M., and Shephard, N. (1999), “Filtering via Simulation: Auxiliary Particle Filters,” *Journal of the American Statistical Association*, 94, 590–599. [105]
- Rasmussen, C. E., and Williams, C. K. I. (2006), *Gaussian Processes for Machine Learning*, Cambridge, MA: The MIT Press. [102]
- Santner, T. J., Williams, B. J., and Notz, W. I. (2003), *The Design and Analysis of Computer Experiments*, New York: Springer-Verlag. [102,108,112]
- Seo, S., Wallat, M., Graepel, T., and Obermayer, K. (2000), “Gaussian Process Regression: Active Data Selection and Test Point Rejection,” in *Proceedings of the International Joint Conference on Neural Networks*, Vol. III, IEEE, pp. 241–246. [103]
- Stein, M. L. (1999), *Interpolation of Spatial Data*, New York: Springer. [103]
- Taddy, M., Lee, H. K. H., Gray, G. A., and Griffin, J. D. (2009), “Bayesian Guided Pattern Search for Robust Local Optimization,” *Technometrics*, 51, 389–401. [103,114]
- Ward, J., and Ripley, B. (1987), “Problems With Likelihood Estimation of Covariance Functions of Spatial Gaussian Processes,” *Biometrika*, 74 (3), 640–642. [104]
- Williams, B., Santner, T., and Notz, W. (2000), “Sequential Design of Computer Experiments to Minimize Integrated Response Functions,” *Statistica Sinica*, 10, 1133–1152. [114]