

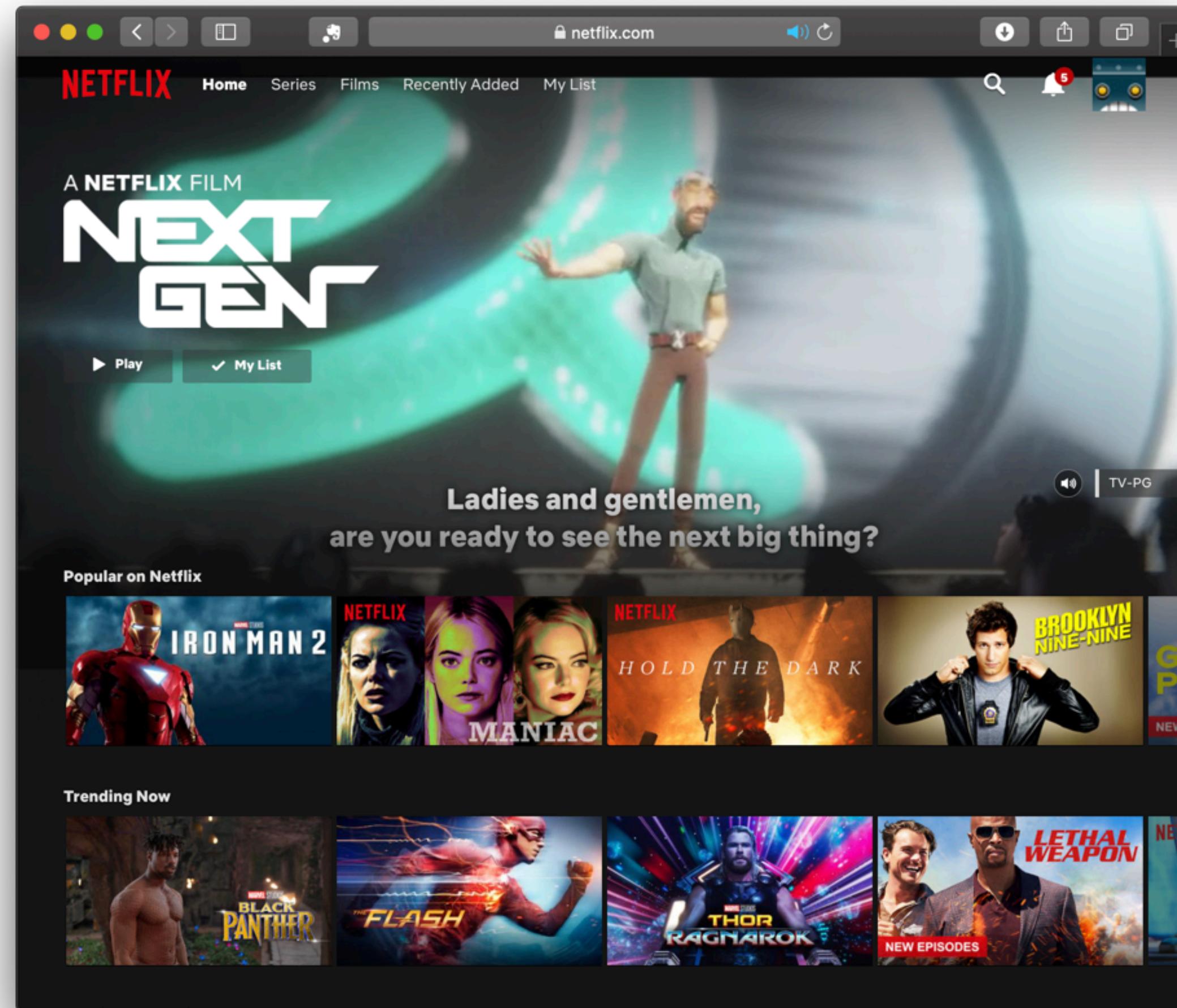
ACM RECSYS 2018

GENERATION MEETS RECOMMENDATION:

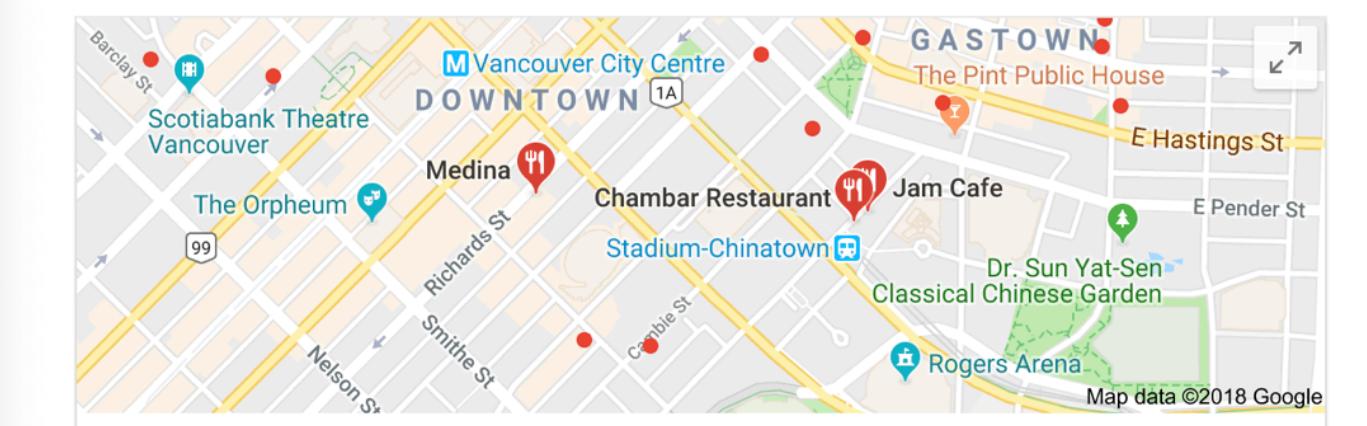
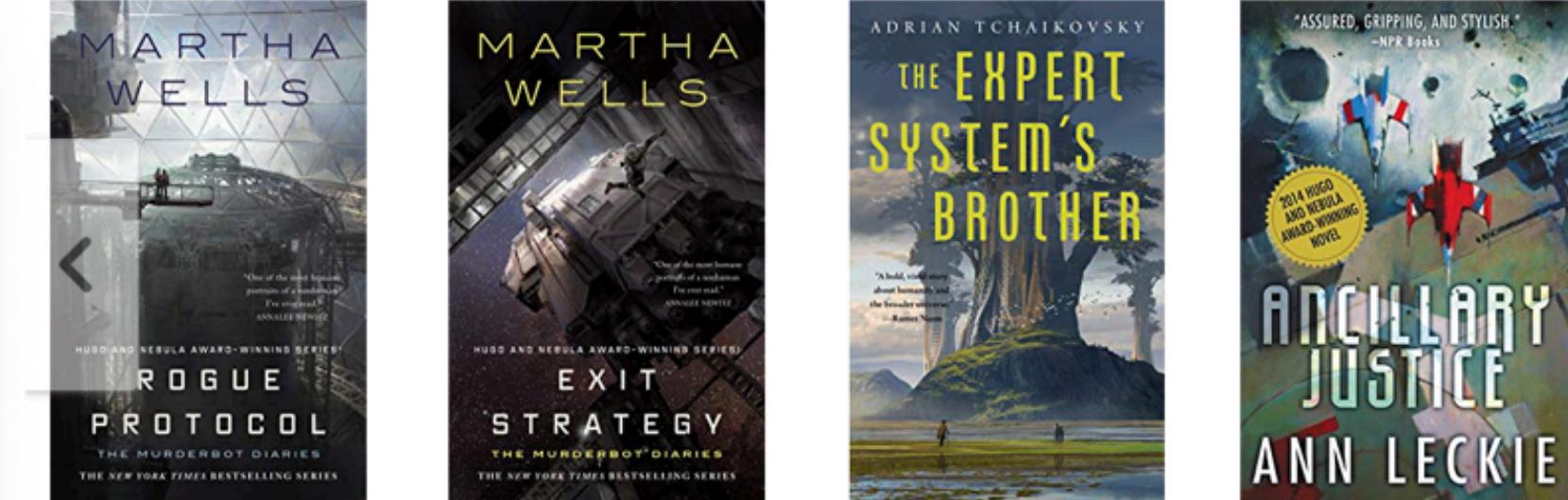
Proposing Novel Items for Groups of Users

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Recommender Systems for Consumers



Recommendations for you in Kindle Store



Rating ▾ Cuisine ▾ Hours ▾ Visit history ▾

Chambar Restaurant

4.4 ★★★★★ (1,567) · \$\$\$ · Restaurant
 Brasserie for mussels & Belgian beers
 568 Beatty St
 Late-night food · Breakfast · Outdoor seating



Jam Cafe

4.6 ★★★★★ (1,039) · \$\$ · Brunch
 556 Beatty St
 Closed · Opens 8 a.m. Thu.



Medina

4.5 ★★★★★ (1,562) · \$\$ · Breakfast
 Eclectic daytime eats & Belgian waffles
 780 Richards St
 Closed · Opens 8 a.m. Thu.



[More places](#)

Makers Recommender Systems for ~~Consumers~~



School of Computing



Makers Recommender Systems for Consumers

II. BACKGROUND AND RELATED WORK

Research into trust in robots (and at a large) interdisciplinary endeavor spanning many human-factors, psychology, and human-computer interaction. It is not possible to cover the breadth of this focus on key concepts and computation.

Key Concepts and Definitions. Trust is a concept, with many factors characterizing it, e.g., the human's technical competence, the robot's performance, the complexity of the robot [15, 19, 11]. One of the most prominent are the performance of the robot and the user's perception of it. Similar to existing work, we assume that robots are not intentionally designed to perform tasks, but rather on characterizing trust based on the user's perception of the robot's performance. Trust as a belief in the competence of the robot is often used to describe the user's intention to complete a task.

Trust Measurement. Trust is a key concept in robotics, but there are many challenges for measuring it. Several surveys have been conducted to derive instruments for measuring trust, including time-varying and static measures [8, 38]. In this paper, we propose a new measure of trust (similar to [36]) and Multi-Task Learning (MTL) to predict trust.

Computational Models of Trust. There are two main types of explanatory models (e.g., [3, 11]): (i) rule-based models and (ii) probabilistic models. Recent models have focused on rule-based models, for example, a recent prediction model for the Dynamic Bayesian Network [9]. A rule-based model is trained on data gathered from various sources and can be used to predict the outcome of a task. For example, a rule-based model was shown to outperform a rule-based model for the Average Value (ARMAV) task [37]. Because trust is a complex concept, rule-based models are often used in these models, they are applied to specific tasks (e.g., trust in robots). However, rule-based models have little variation. How can we generate novel items that capture both the variation across tasks and the variation within tasks? This is a challenging problem because rule-based models have been previously used to predict trust in robots.

Application of Trust. Trust is a key concept in collaborative settings, such as recommendation systems. For example, Miao et al. proposed a model that incorporates trust into a recommendation system that predicts better outcomes. The model is integrated into such systems and has been previously used to predict trust in robots.

III. RELATED WORK

In this section, we review related work that was designed to address the challenges between tasks. Our work focuses on the intersection of recommendation systems and robotics.

IV. CONCLUSION

We have presented a framework for generating novel items for groups of users. Our approach relies on two related components: (i) a shared latent representation space learned from user-item rating data and (ii) a pair of functions: the encoder $f_e(x)$ that maps item features x to their respective latent representations/embeddings z , and a decoder $g_e(z)$ that performs the inverse operation, i.e., maps embeddings z to item features x . We exploit this space to obtain novel items with high predicted desirability through greedy weighted maximum coverage, and then generate item features via the decoder.

ACKNOWLEDGMENTS

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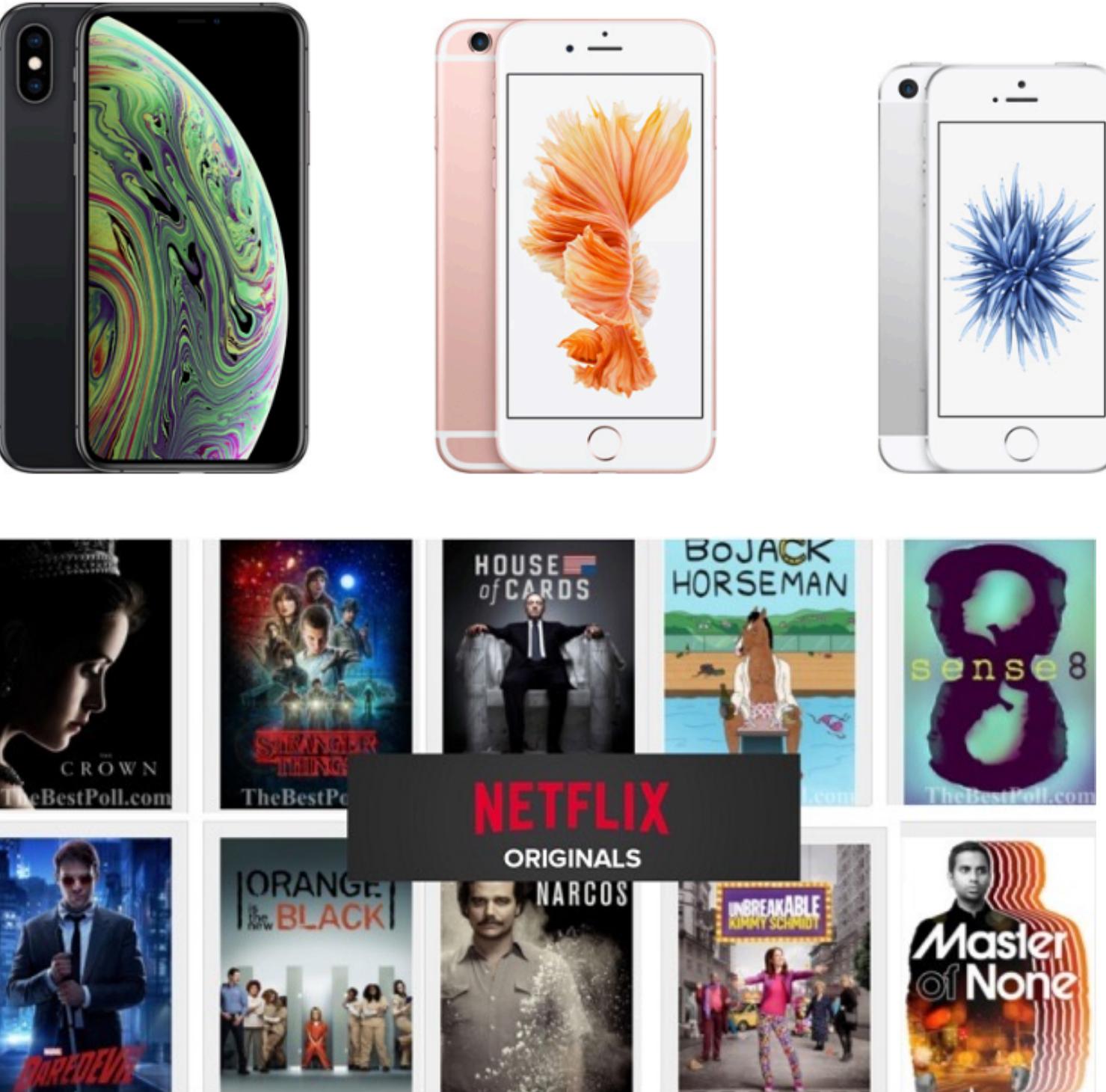
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[46] T. V. Vo and H. Soh. Generation Meets Recommendation: Proposing Novel Items for Groups

Makers Recommender Systems for Consumers



Makers Recommender Systems for ~~Consumers~~

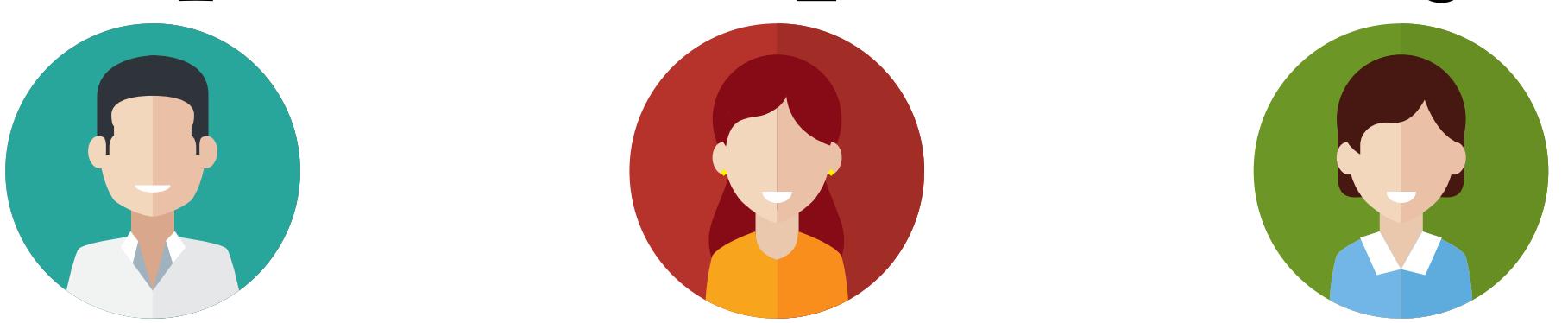
- **What set of products** would appeal to a wide range of people?
- **Who** would like those products?
- **How many** products should you make?



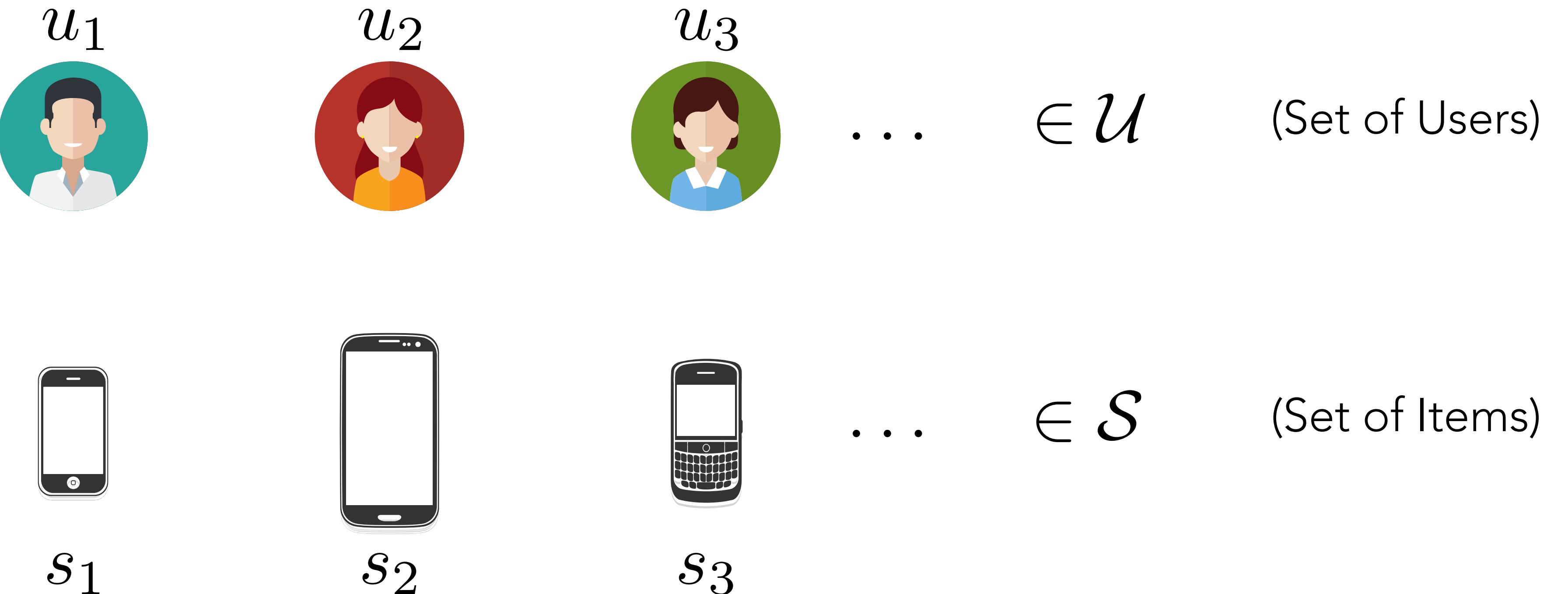
Formalized problem & developed methods to jointly address these Questions

Formalizing the Problem

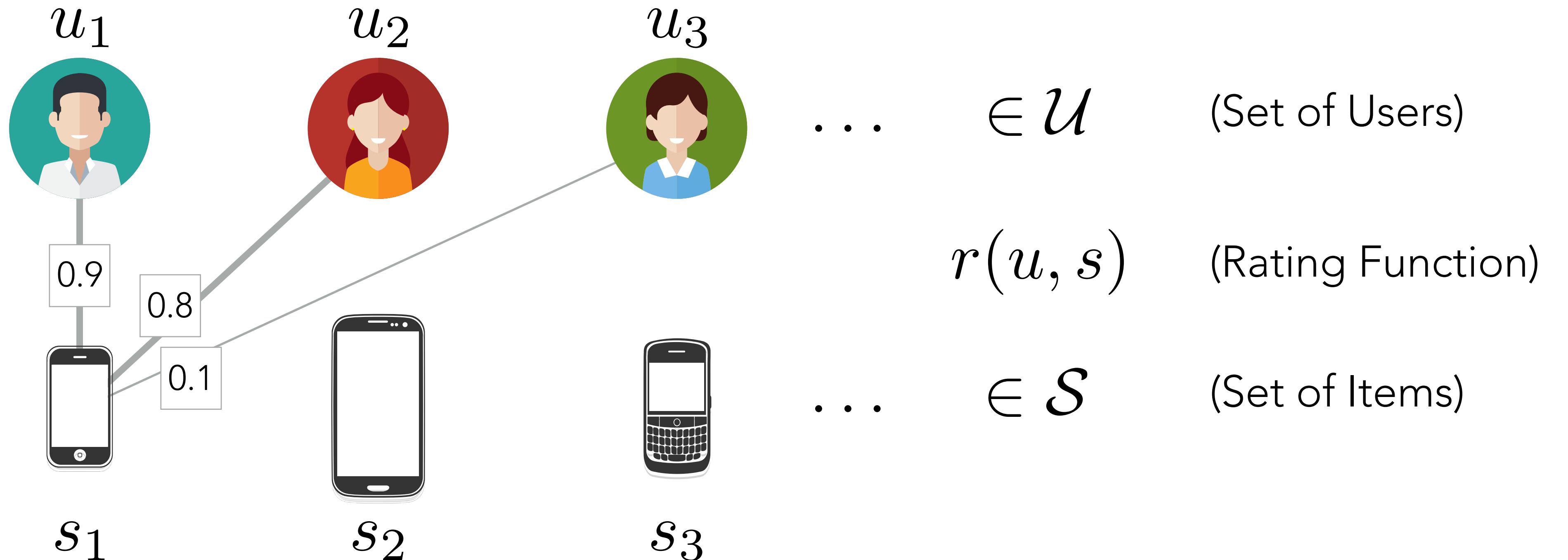
u_1 u_2 u_3 ... $\in \mathcal{U}$ (Set of Users)



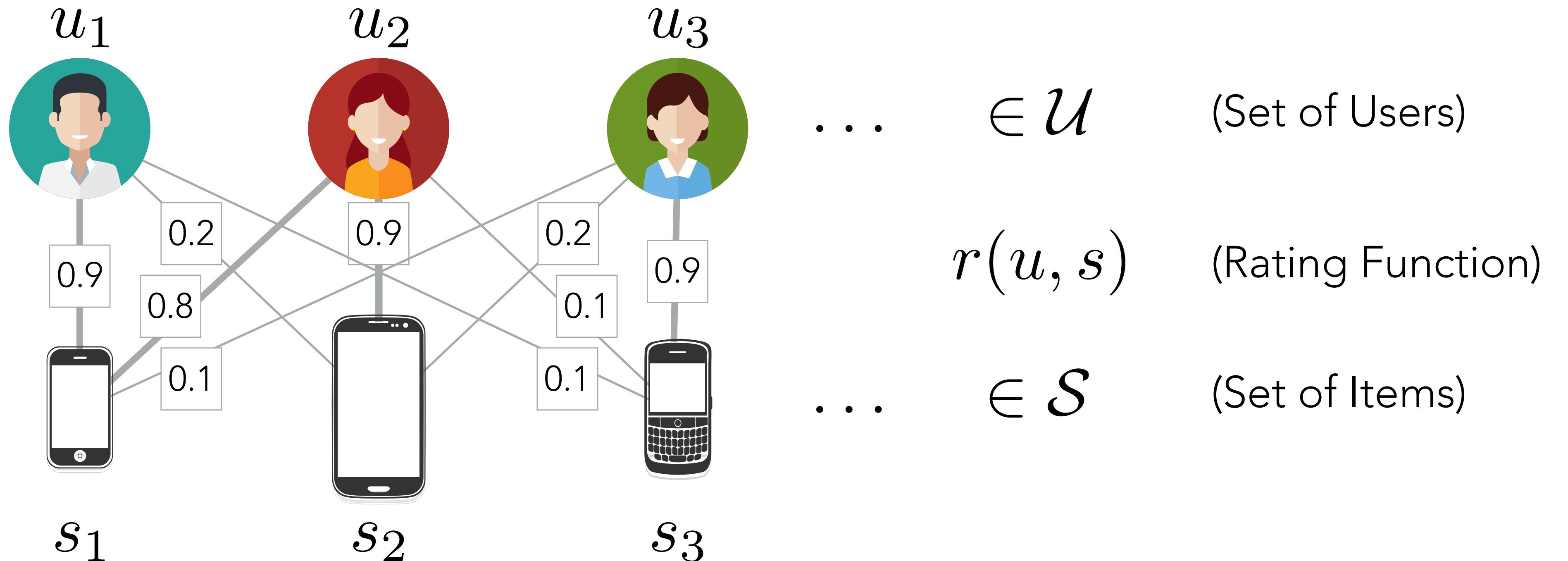
Formalizing the Problem



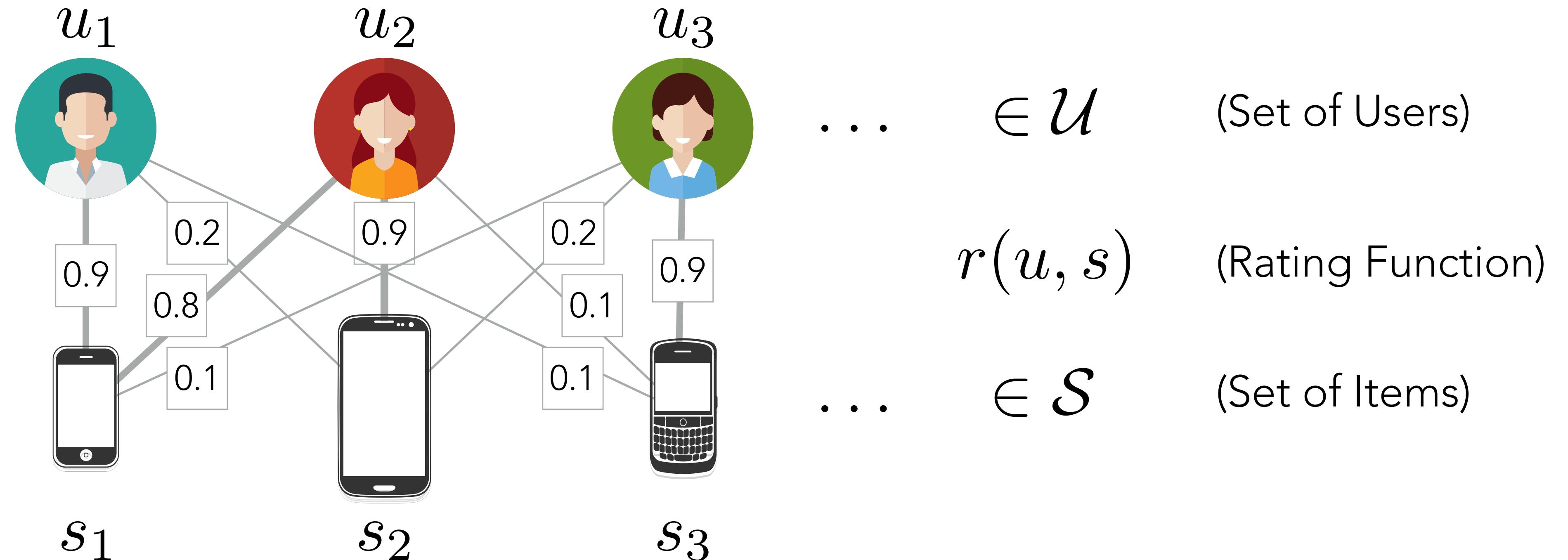
Formalizing the Problem



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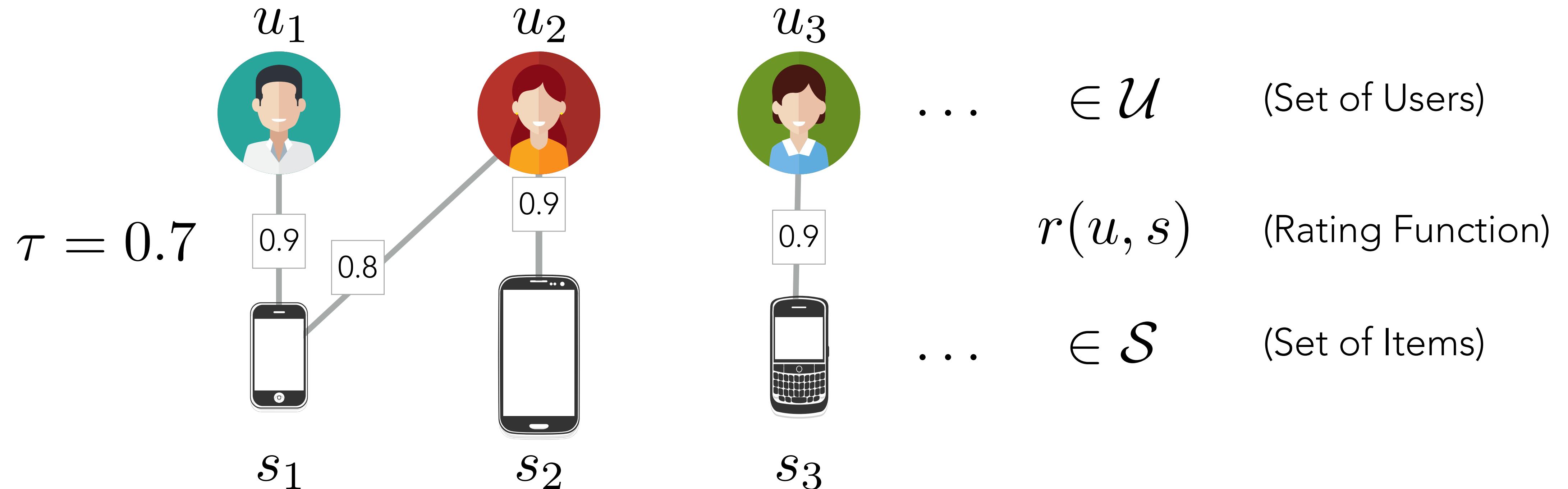


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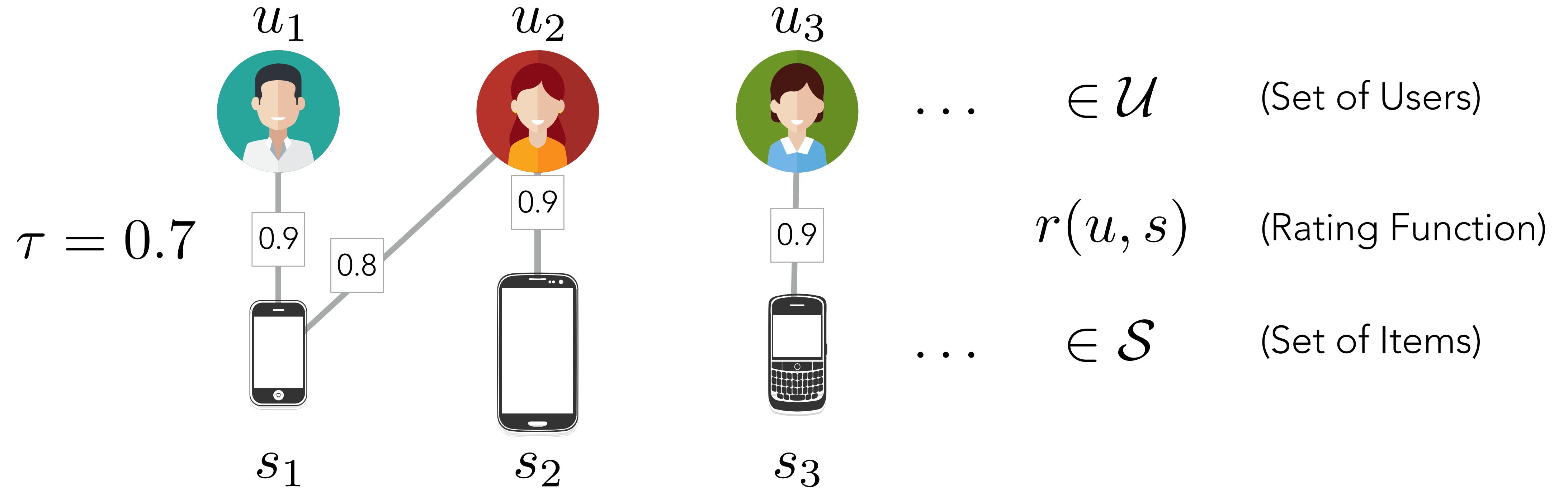
“Cover” $c(u, s) = \begin{cases} 1 & \text{if } r(u, s) > \tau \text{ (above threshold)} \\ 0 & \text{otherwise} \end{cases}$

Formalizing the Problem



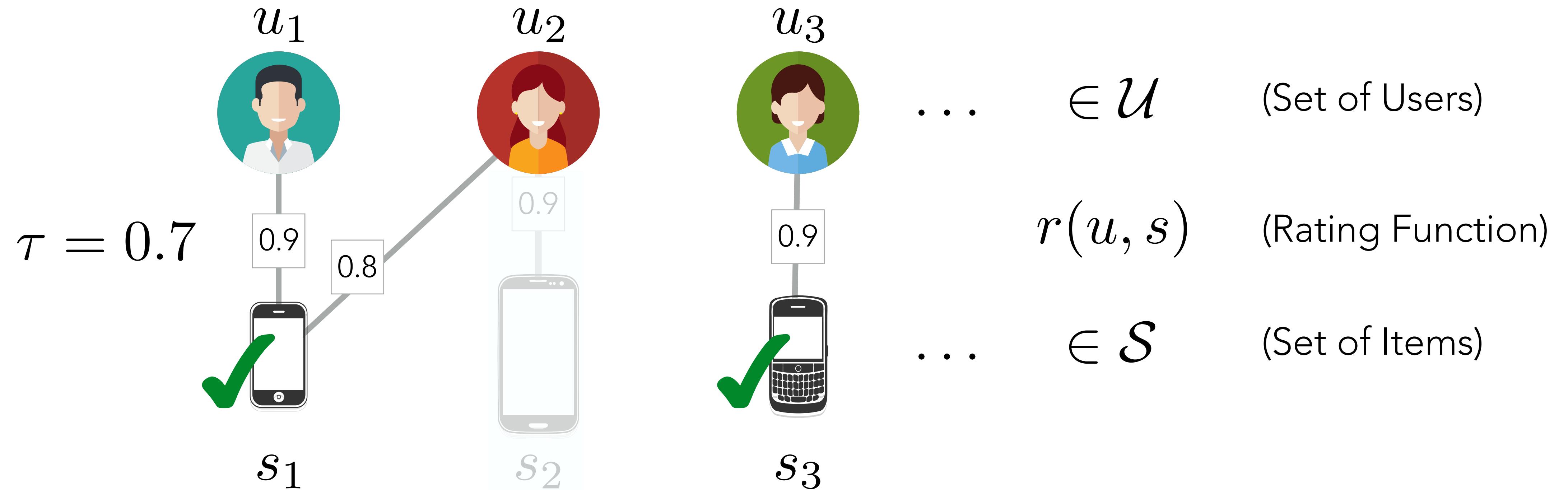
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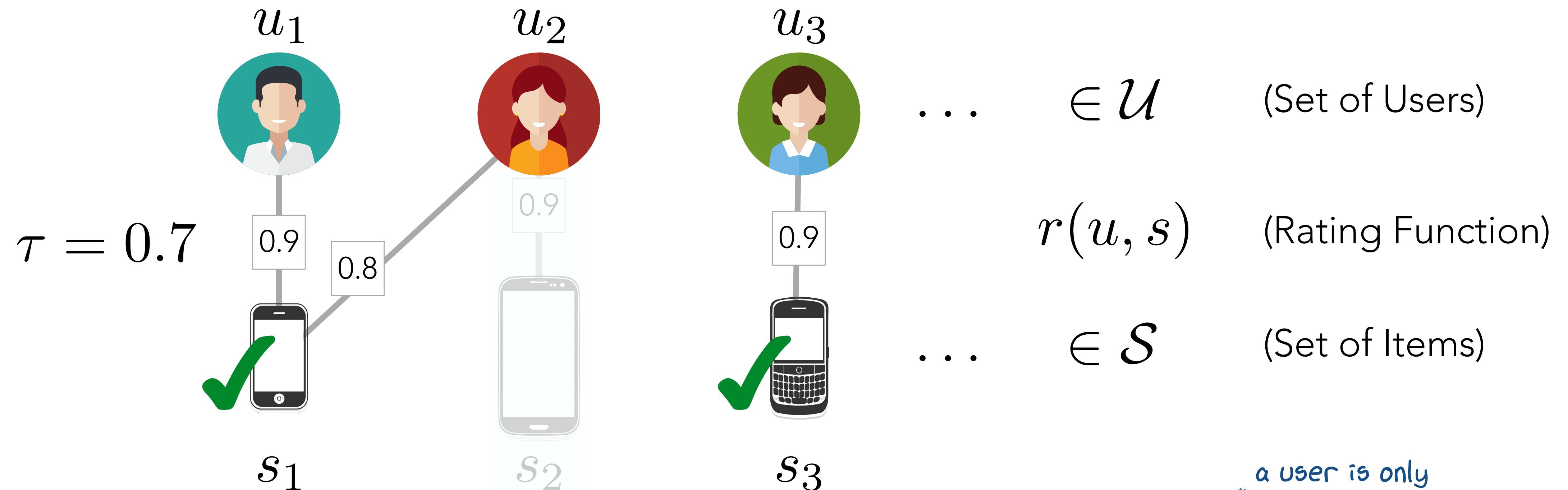
if $k = 2$ (can only pick 2 items), which would you pick?

Formalizing the Problem



if $k = 2$ (can only pick 2 items), which would you pick?

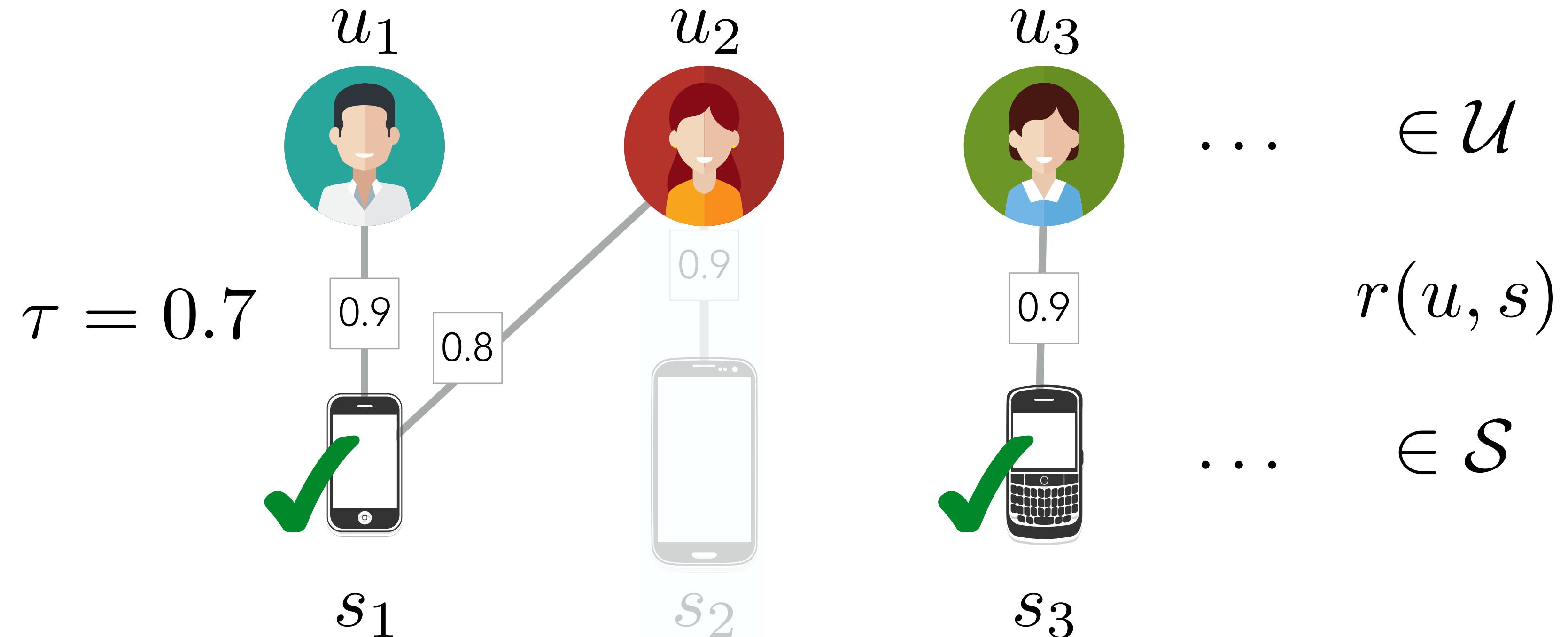
Formalizing the Problem



$$\operatorname{argmax}_{\mathcal{V} \subseteq \mathcal{S}} \sum_{u \in \mathcal{U}} \sum_{v \in \mathcal{V}} r(u, v) c_{uv}$$

such that:
 $\sum_{v \in \mathcal{V}} c_{uv} = 1$ and $|\mathcal{V}| = k$
 a user is only covered by one item
 k items selected

Formalizing the Problem

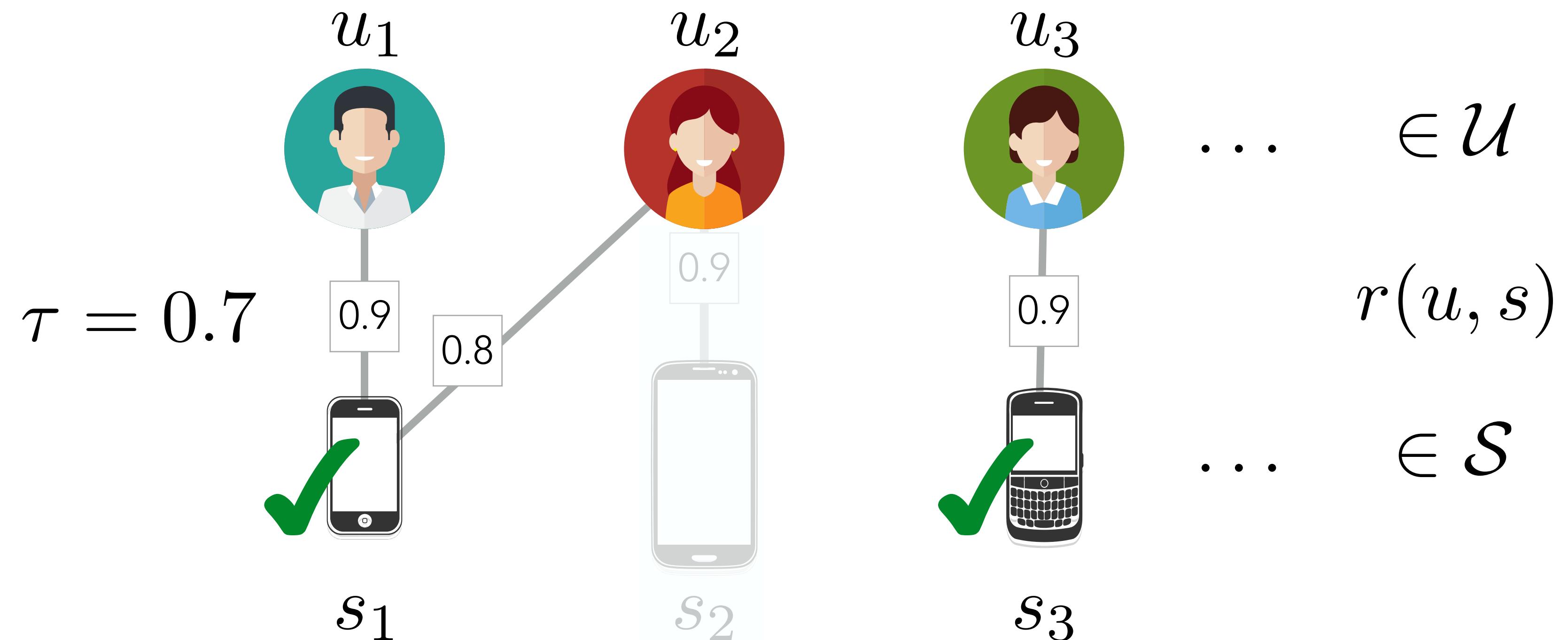


$$\operatorname{argmax}_{\mathcal{V} \subseteq \mathcal{S}} \sum_{u \in \mathcal{U}} \sum_{v \in \mathcal{V}} r(u, v) c_{uv}$$

such that:

$$\sum_{v \in \mathcal{V}} c_{uv} = 1 \text{ and } |\mathcal{V}| = k$$

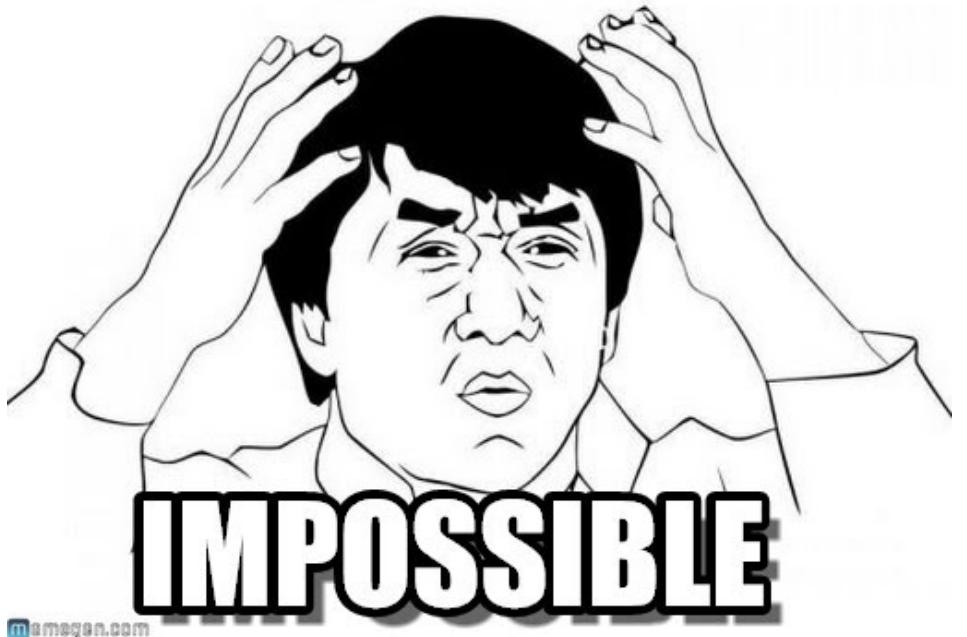
Formalizing the Problem



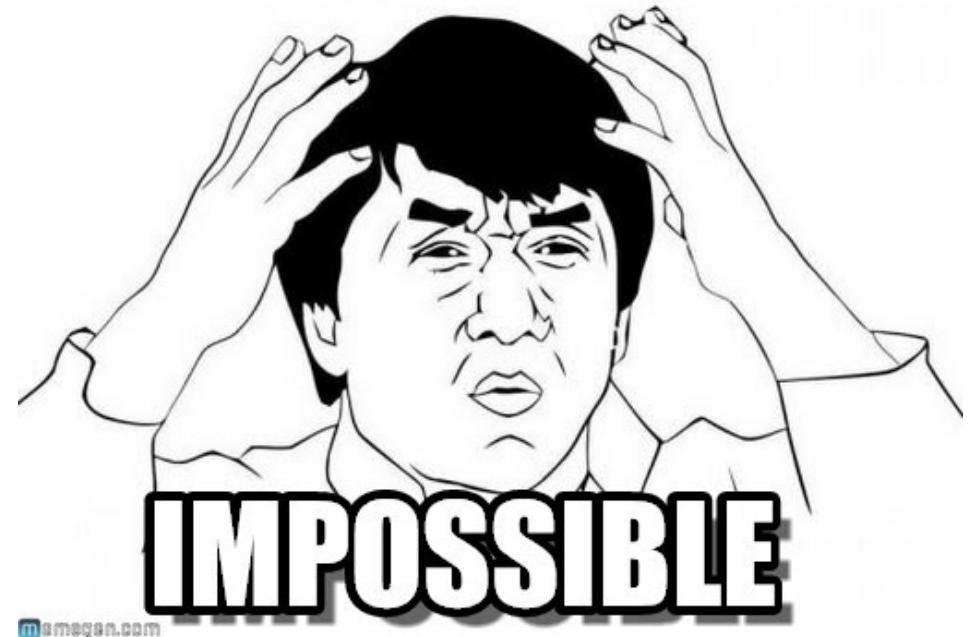
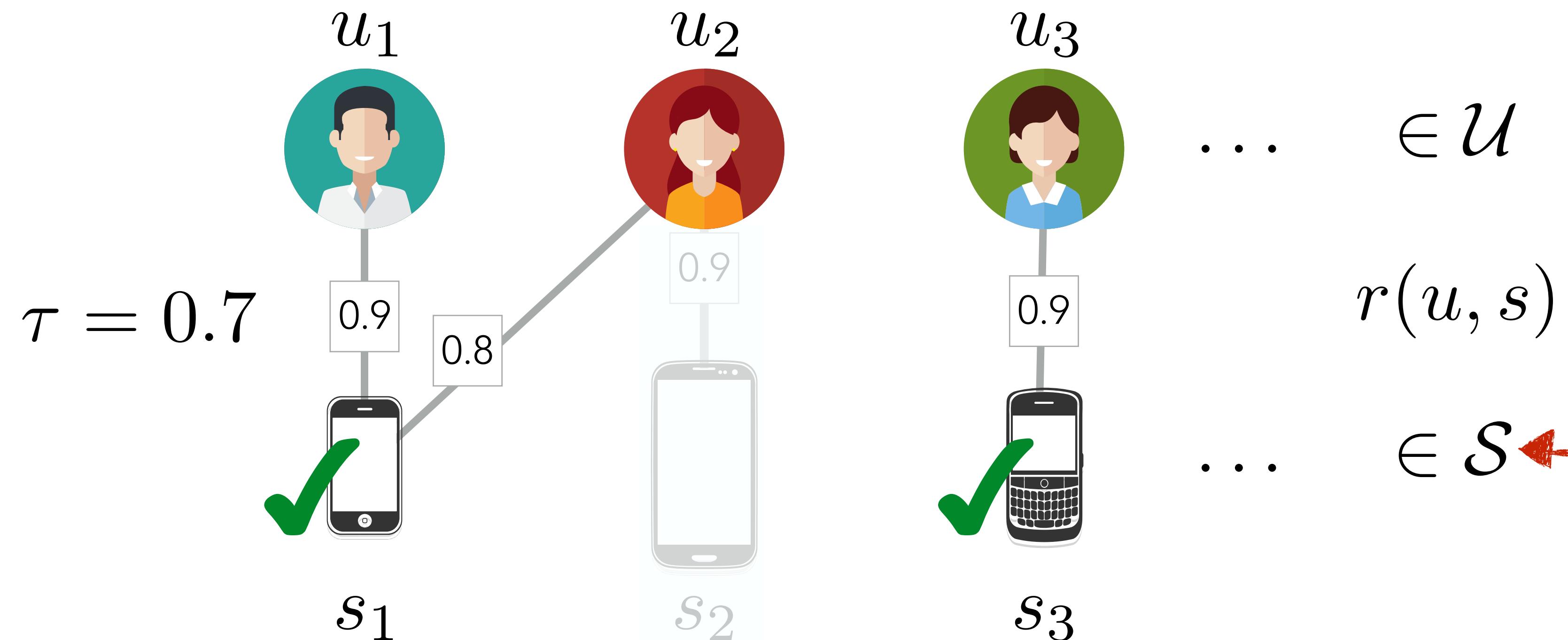
$$\operatorname{argmax}_{\mathcal{V} \subseteq \mathcal{S}} \sum_{u \in \mathcal{U}} \sum_{v \in \mathcal{V}} r(u, v) c_{uv}$$

such that:

$$\sum_{v \in \mathcal{V}} c_{uv} = 1 \text{ and } |\mathcal{V}| = k$$



Formalizing the Problem

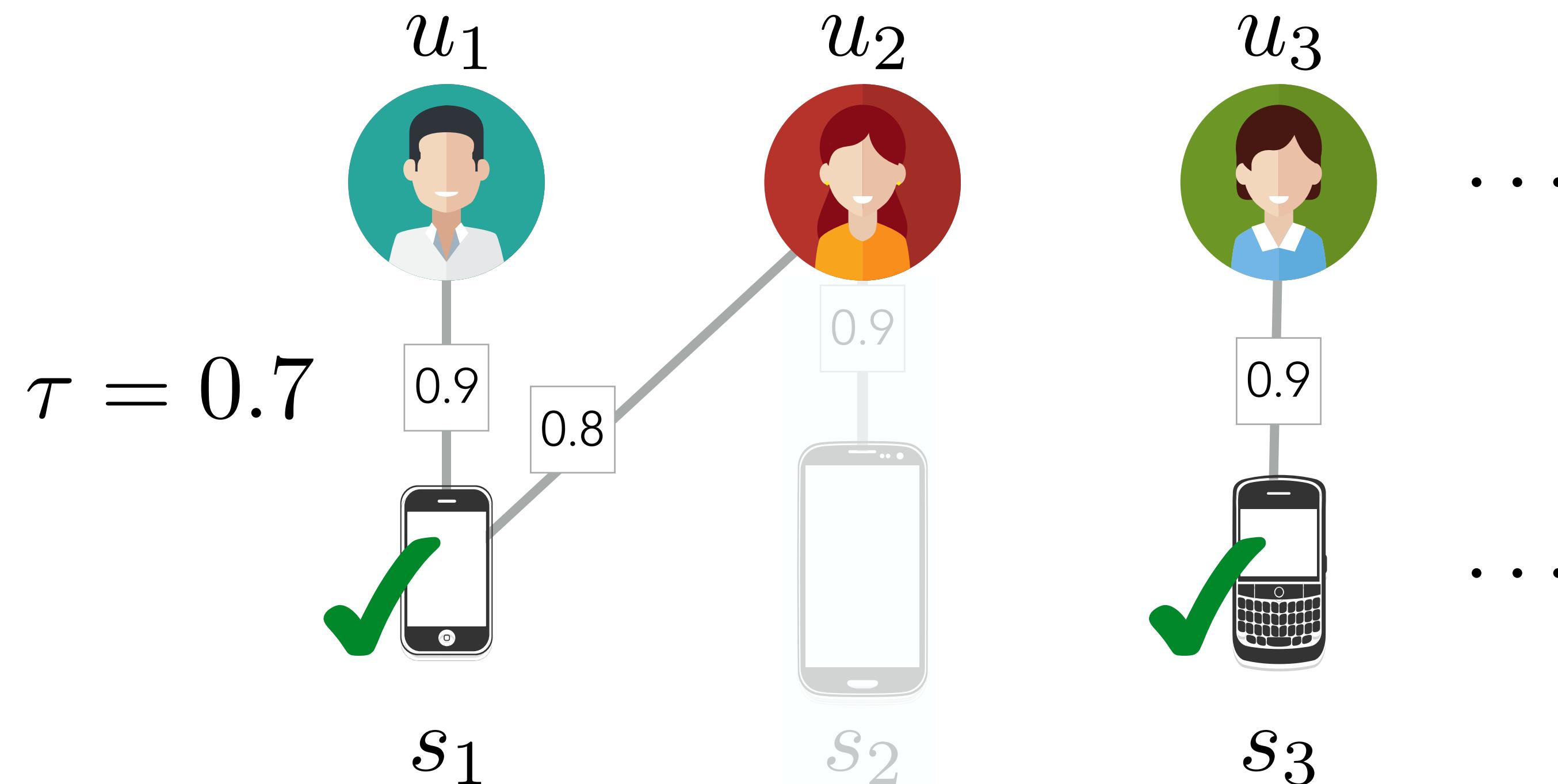
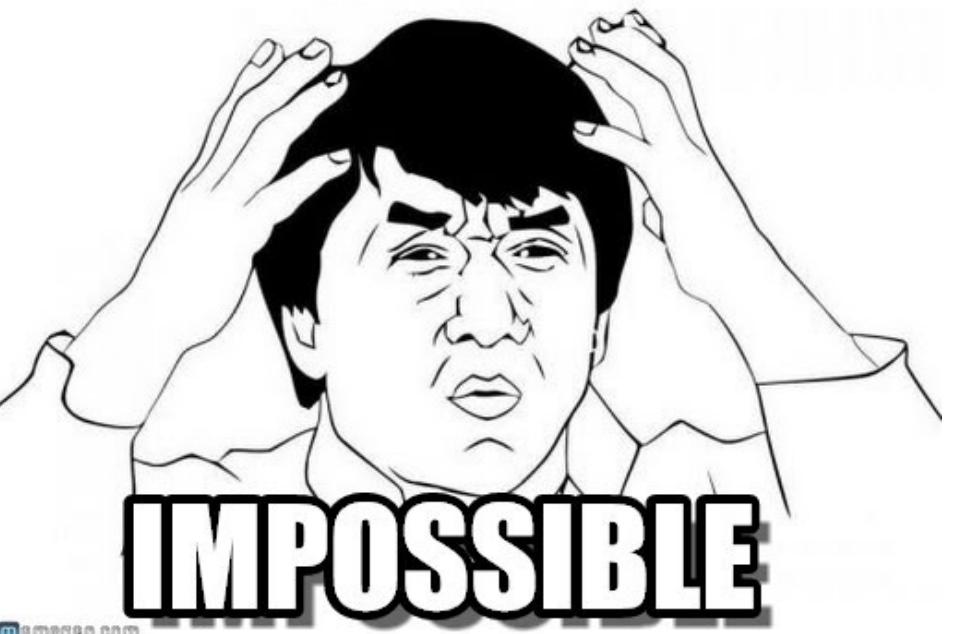

 $r(u, s)$
 $\in \mathcal{S} \leftarrow$ Don't know this.

$$\operatorname{argmax}_{\mathcal{V} \subseteq \mathcal{S}} \sum_{u \in \mathcal{U}} \sum_{v \in \mathcal{V}} r(u, v) c_{uv}$$

such that:

$$\sum_{v \in \mathcal{V}} c_{uv} = 1 \text{ and } |\mathcal{V}| = k$$

Formalizing the Problem


 $\in \mathcal{U}$


$r(u, s) \leftarrow$ Don't have this either.

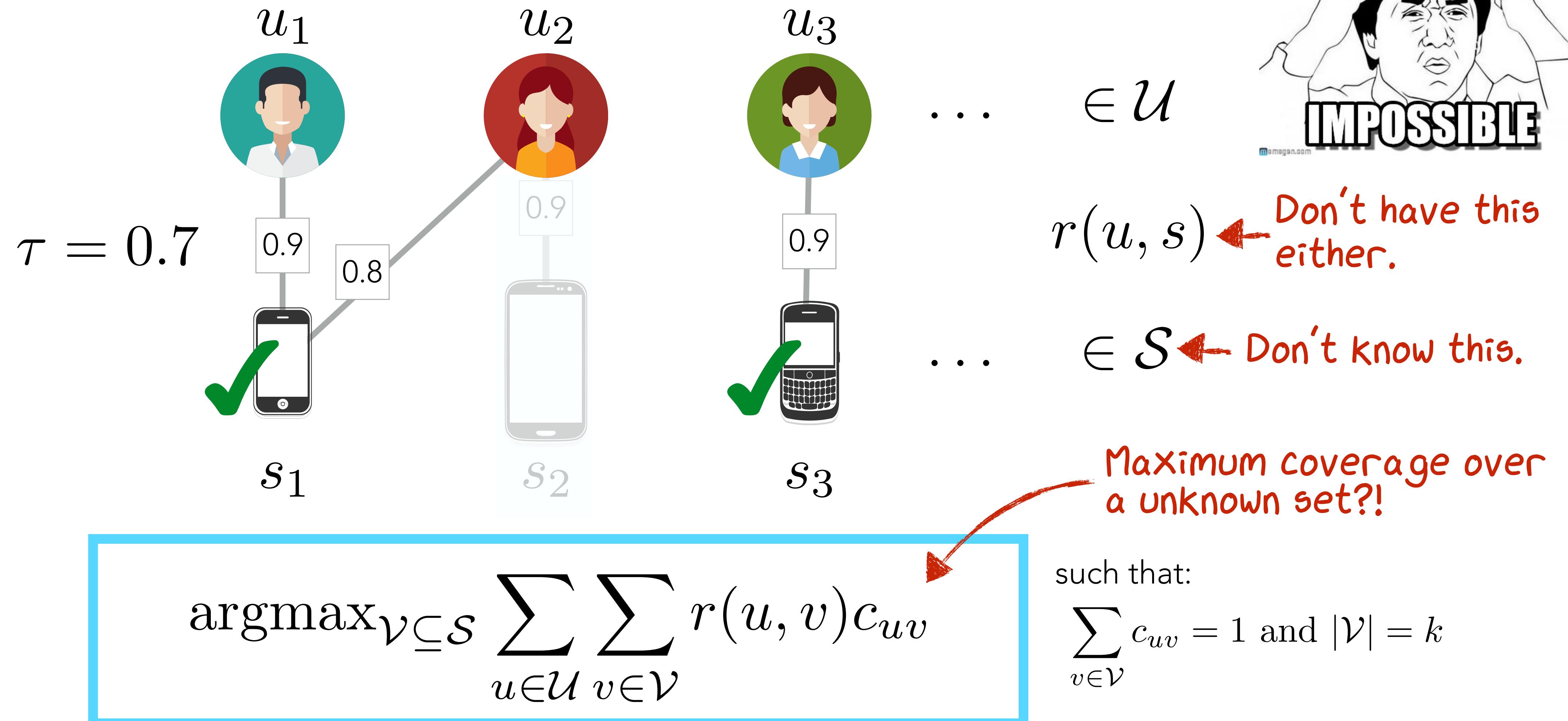
$\in \mathcal{S} \leftarrow$ Don't know this.

$$\operatorname{argmax}_{\mathcal{V} \subseteq \mathcal{S}} \sum_{u \in \mathcal{U}} \sum_{v \in \mathcal{V}} r(u, v) c_{uv}$$

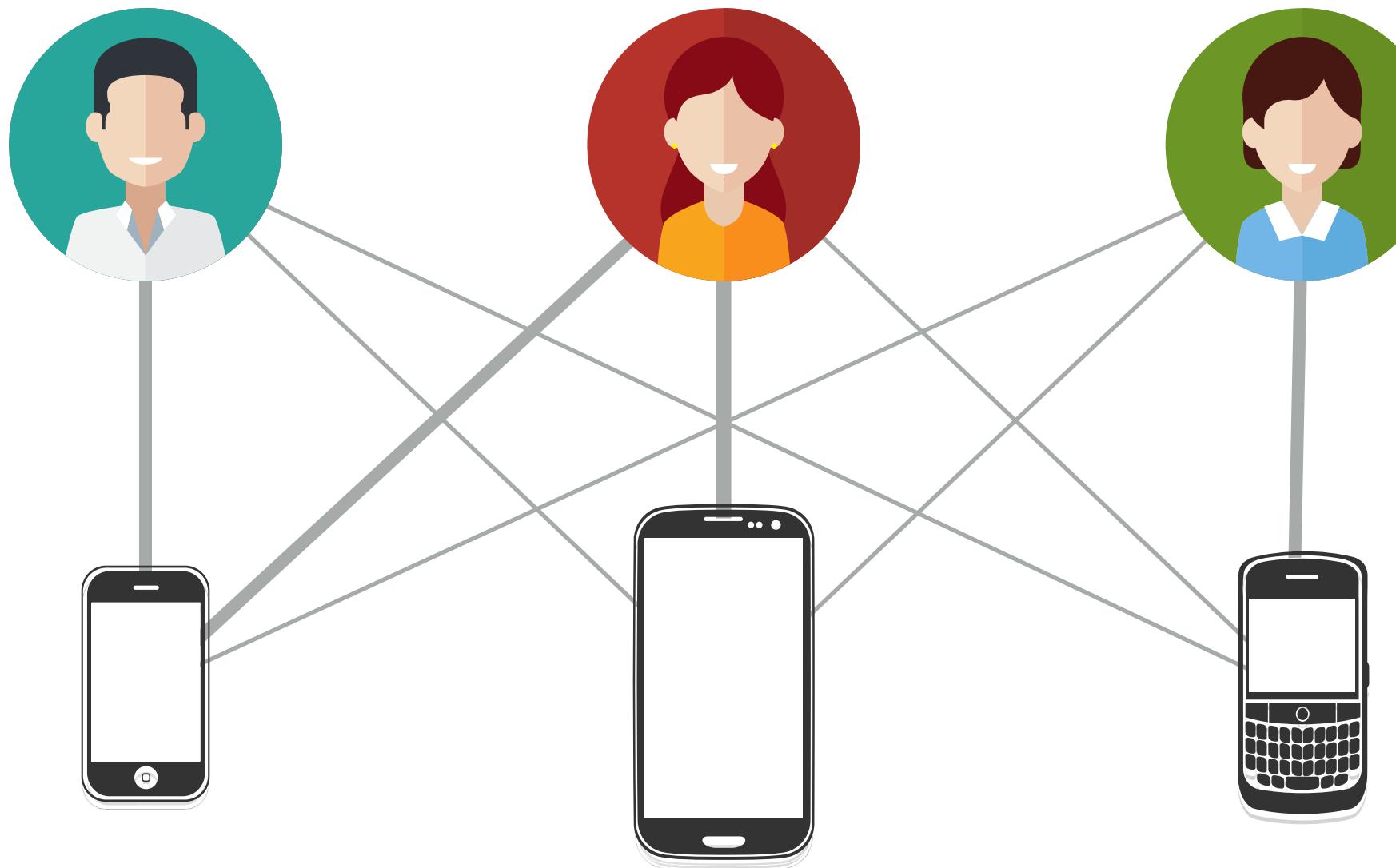
such that:

$$\sum_{v \in \mathcal{V}} c_{uv} = 1 \text{ and } |\mathcal{V}| = k$$

Formalizing the Problem



Re-Formalizing with a Latent Space

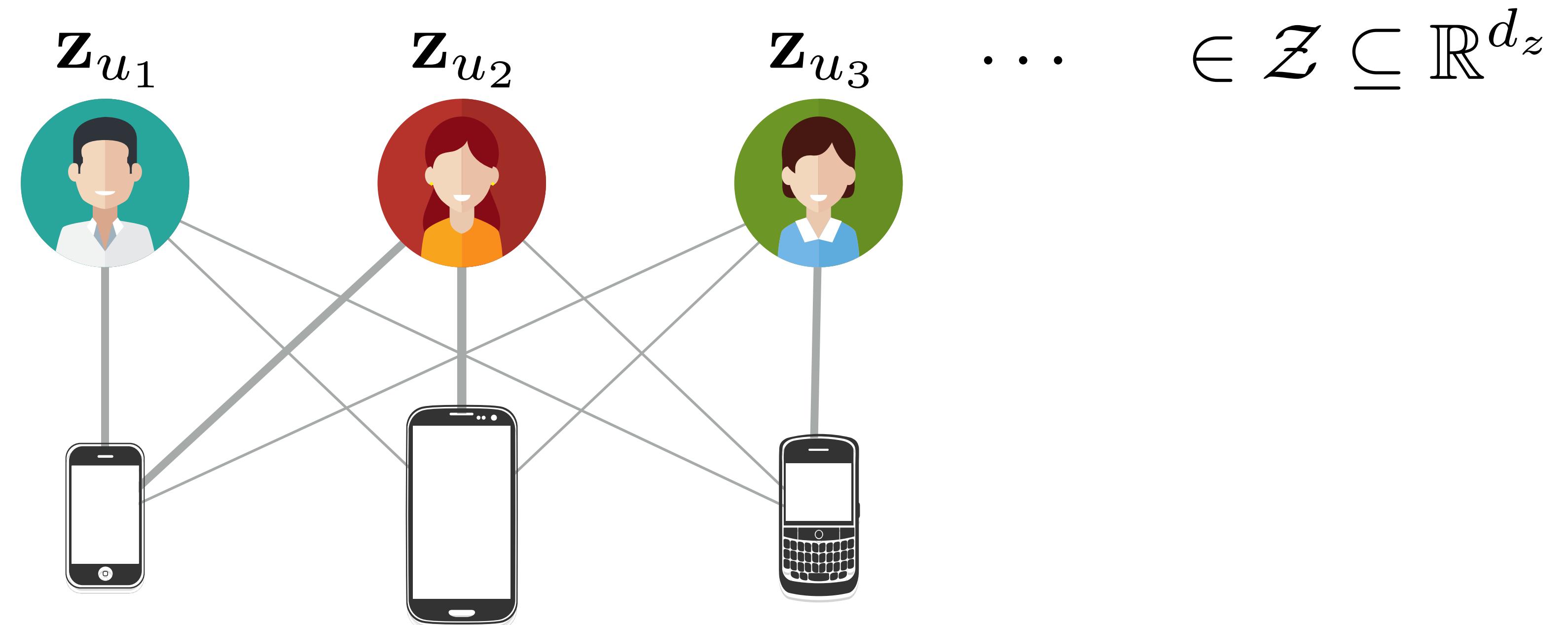


$$\operatorname{argmax}_{\mathcal{V} \subseteq \mathcal{S}} \sum_{u \in \mathcal{U}} \sum_{v \in \mathcal{V}} r(u, v) c_{uv}$$

such that:

$$\sum_{v \in \mathcal{V}} c_{uv} = 1 \text{ and } |\mathcal{V}| = k$$

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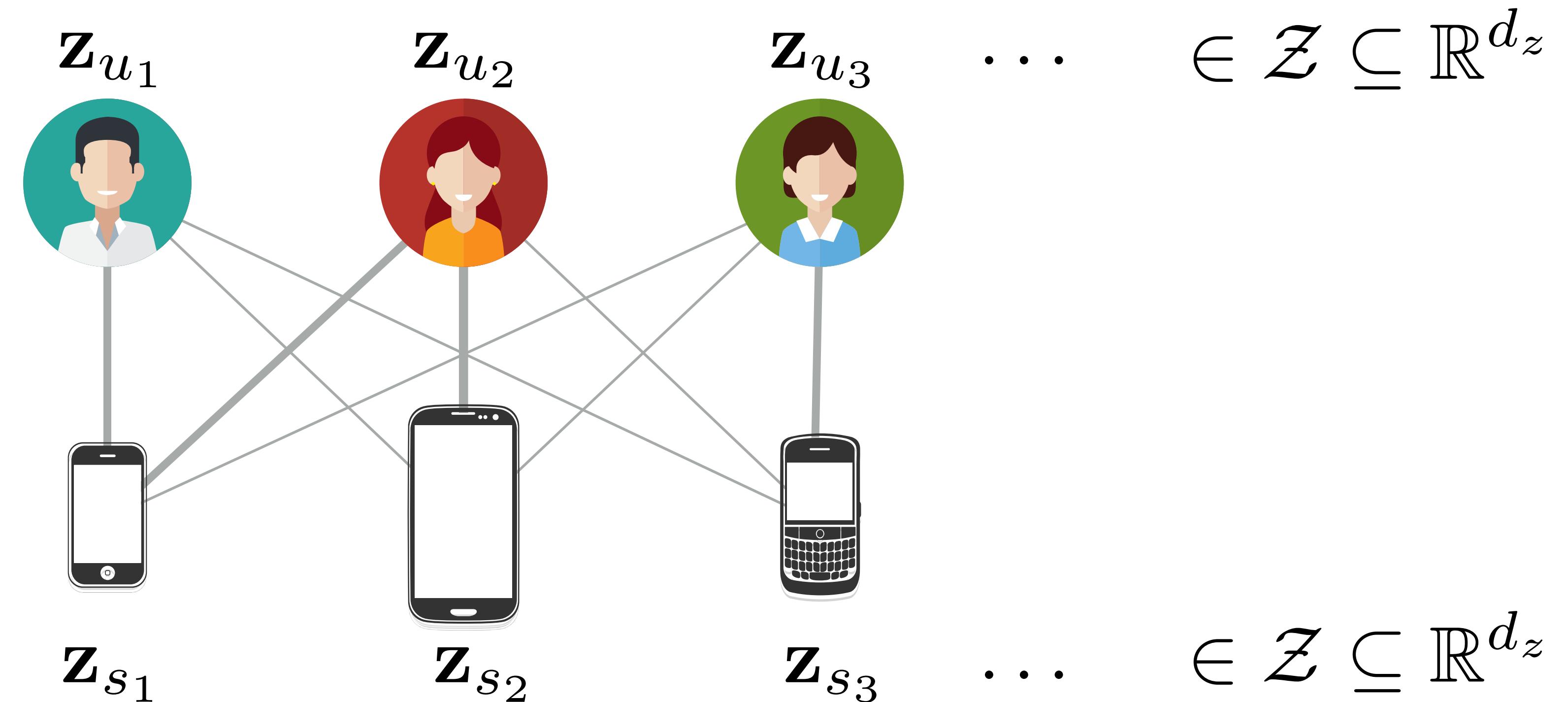


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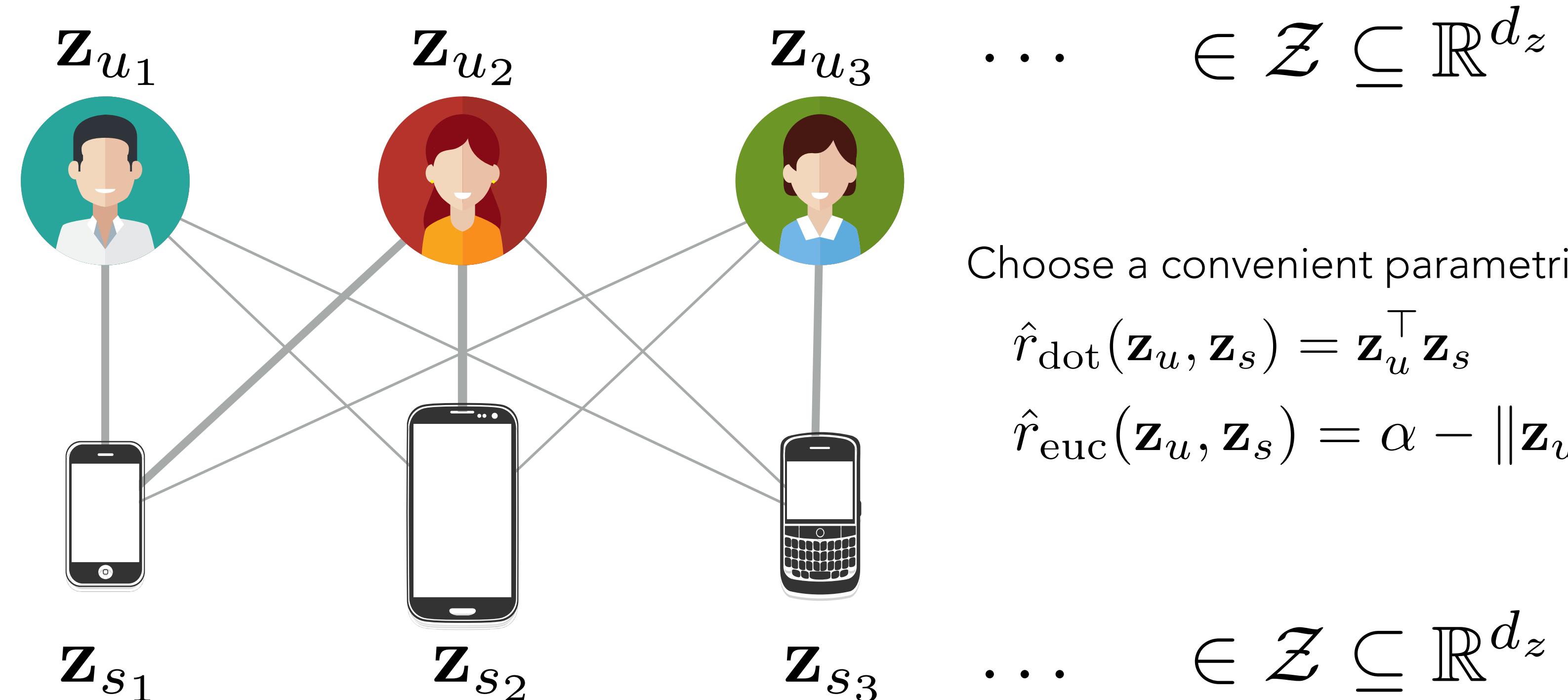


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Re-Formalizing with a Latent Space



Choose a convenient parametric function:

$$\hat{r}_{\text{dot}}(\mathbf{z}_u, \mathbf{z}_s) = \mathbf{z}_u^\top \mathbf{z}_s$$

$$\hat{r}_{\text{euc}}(\mathbf{z}_u, \mathbf{z}_s) = \alpha - \|\mathbf{z}_u - \mathbf{z}_s\|_2$$

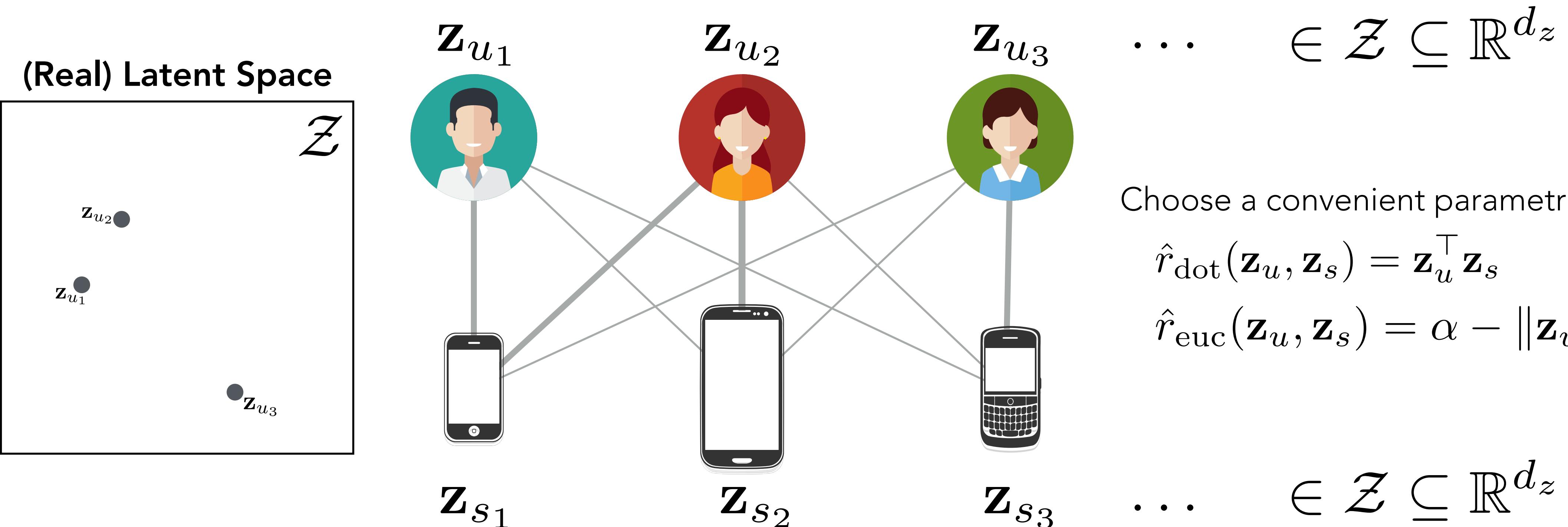
$$\in \mathcal{Z} \subseteq \mathbb{R}^{d_z}$$

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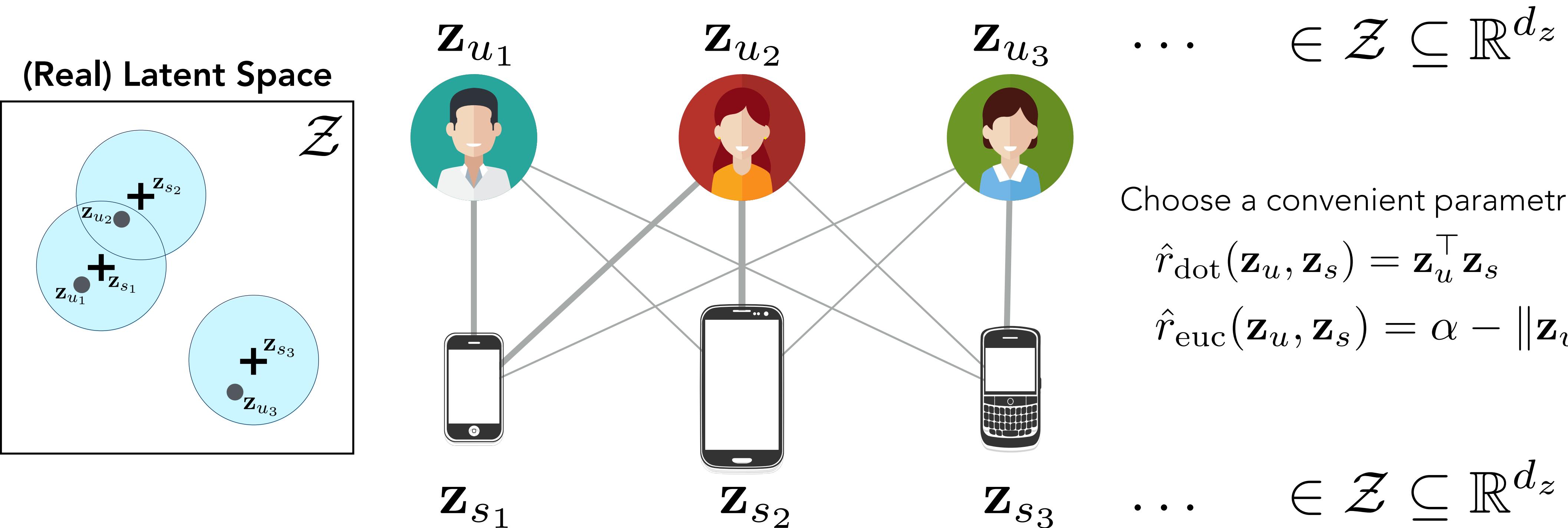
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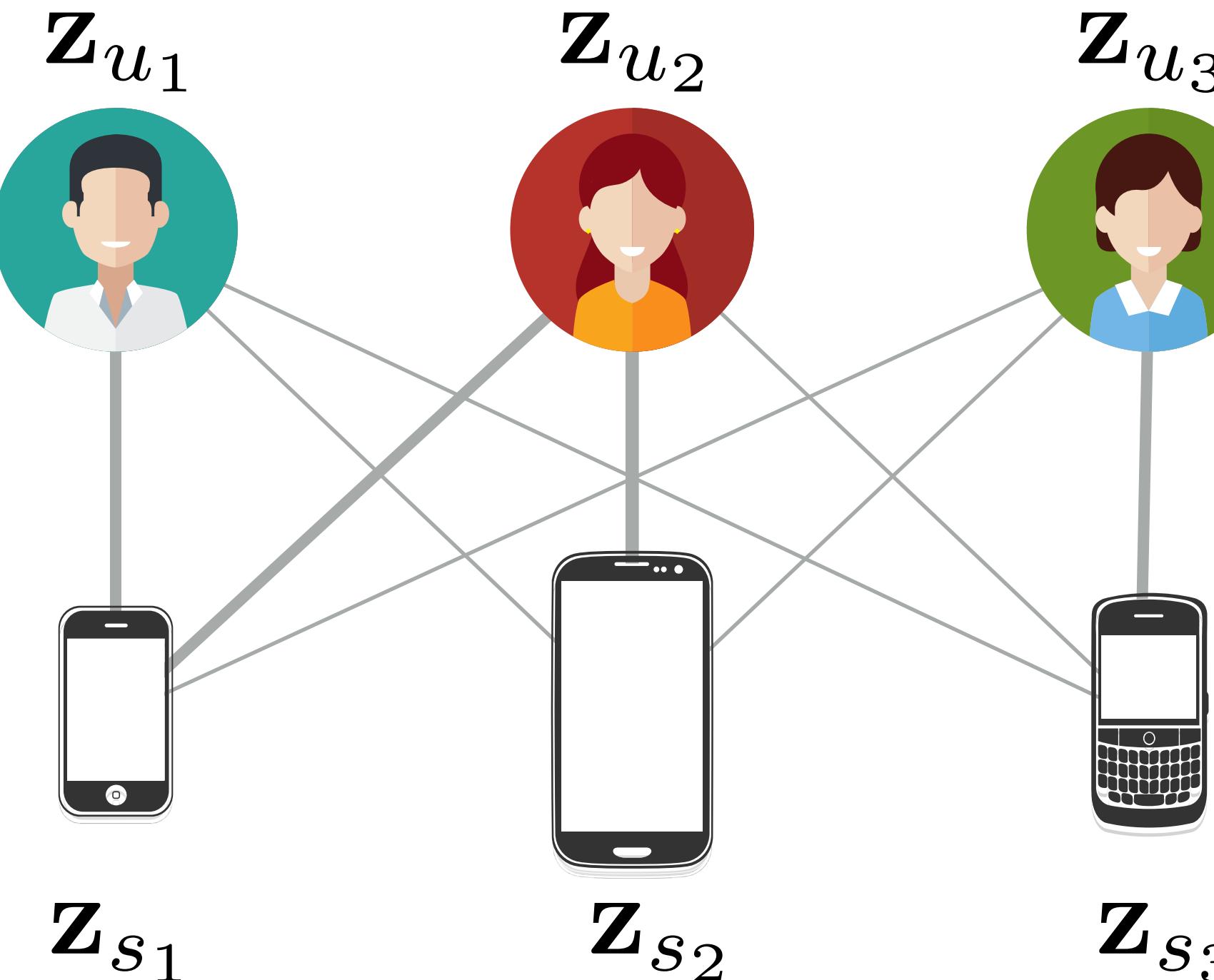
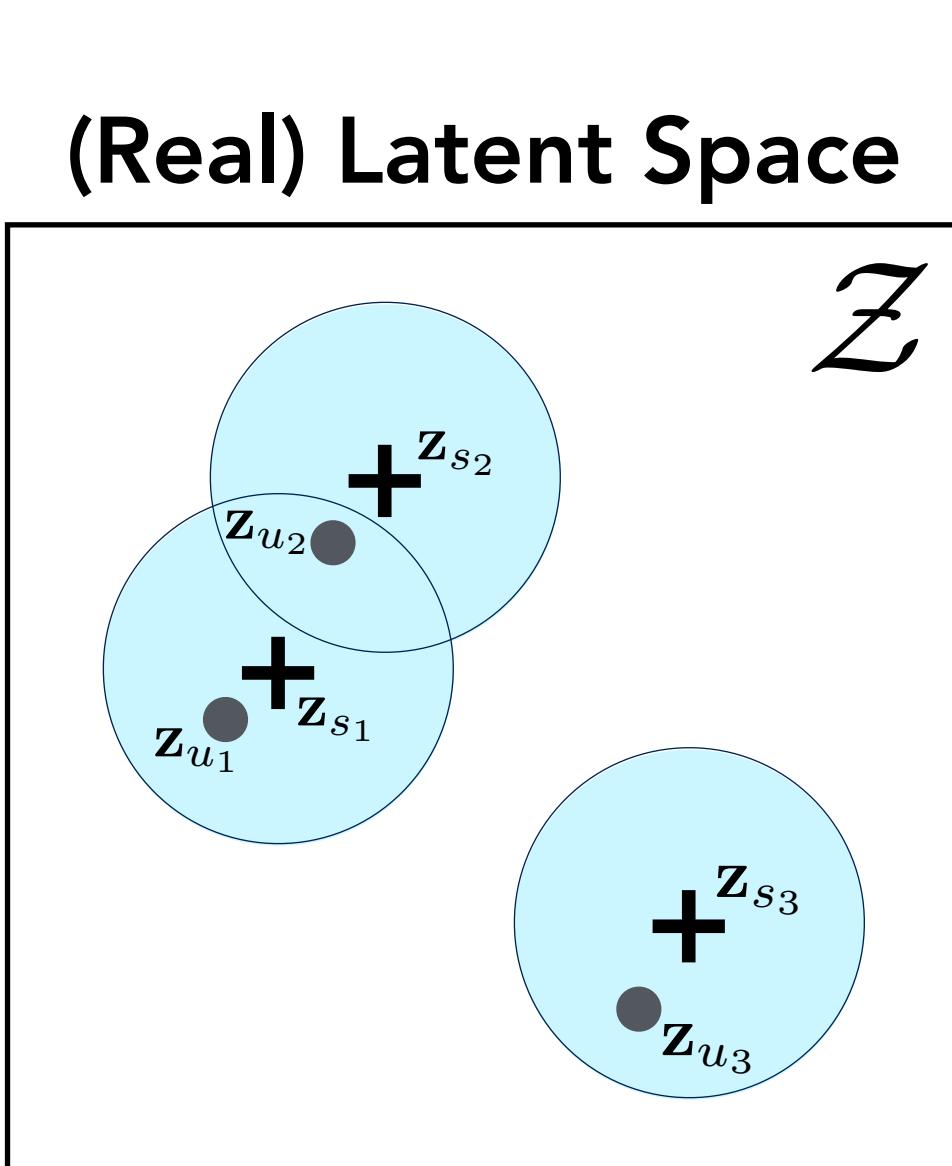


$$\operatorname{argmax}_{\mathcal{V}} \sum_{u \in \mathcal{U}} \sum_{v \in \mathcal{V}} \hat{r}(\mathbf{z}_u, \mathbf{z}_v) c_{uv}$$

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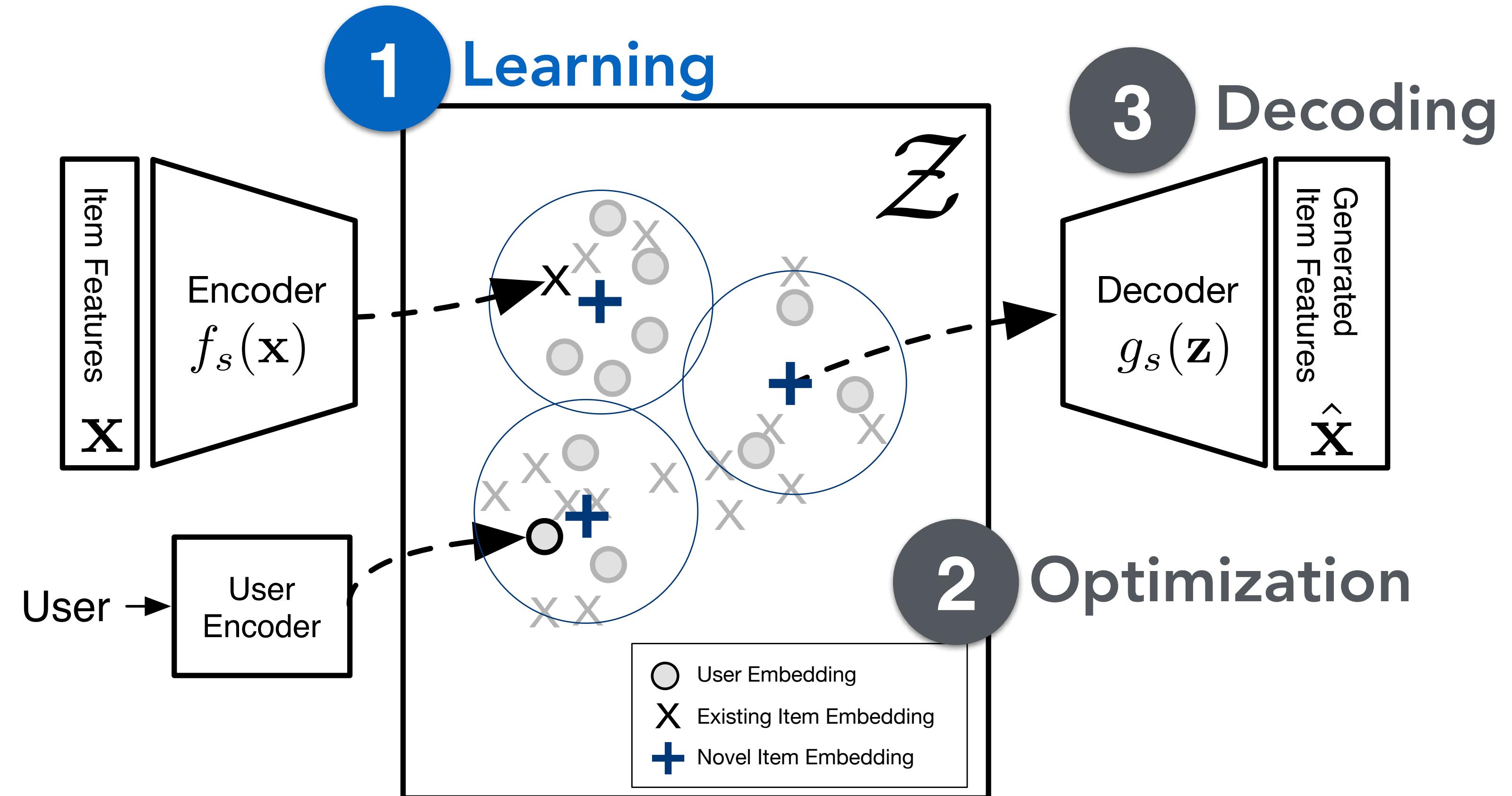


Provided we can learn Z !

$$\operatorname{argmax}_{\mathcal{V}} \sum_{u \in \mathcal{U}} \sum_{v \in \mathcal{V}} \hat{r}(\mathbf{z}_u, \mathbf{z}_v) c_{uv}$$

such that:

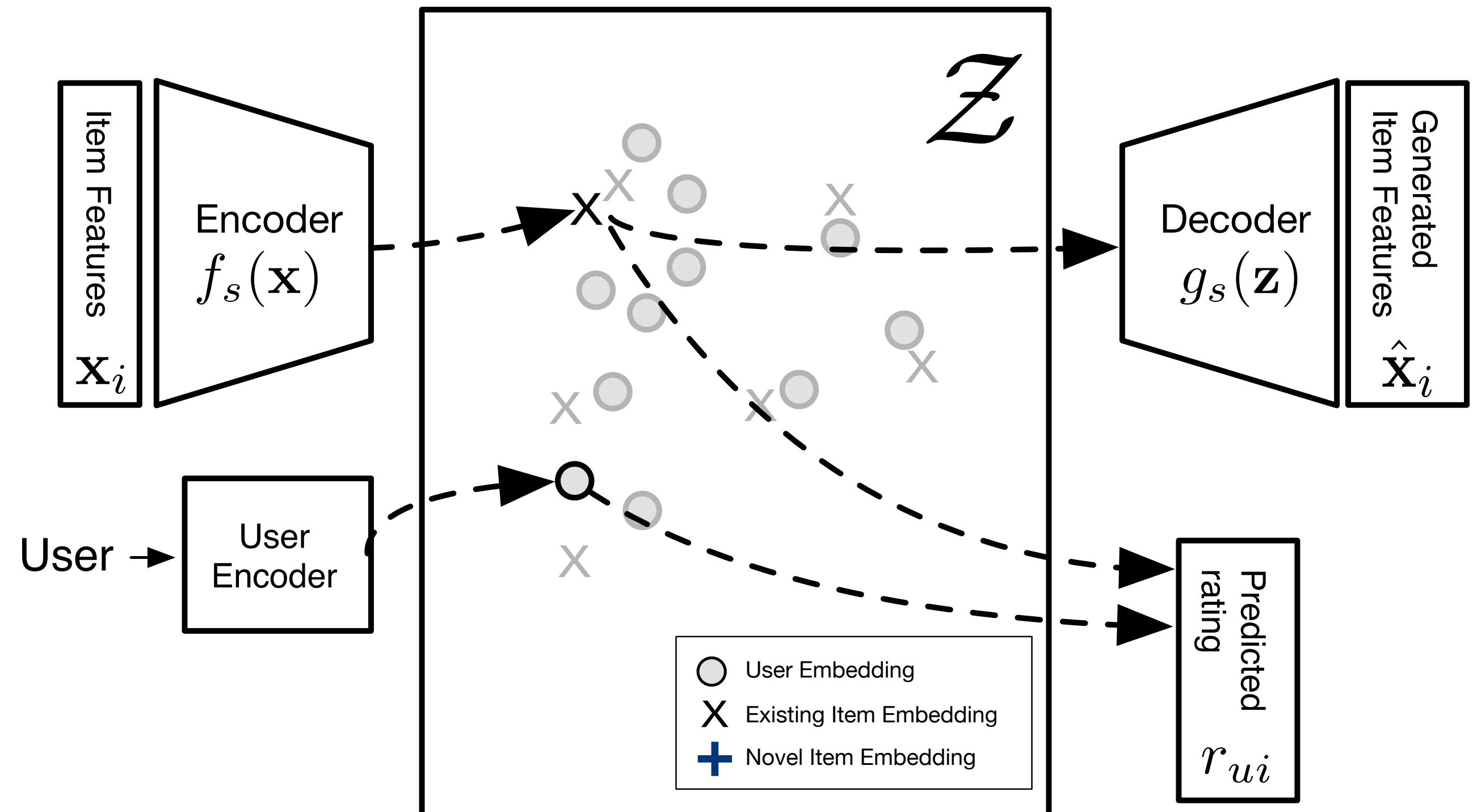
$$\sum_{v \in \mathcal{V}} c_{uv} = 1 \text{ and } |\mathcal{V}| = k$$



$$\mathcal{L} = \text{Rating Loss} + \text{Reconstruction Loss} + \text{Regularizer}$$

$$= \mathcal{L}_r(\theta) + \lambda_1 \mathcal{L}_g(\phi) + \lambda_2 \mathcal{R}(\theta, \phi)$$

Collaborative VAE

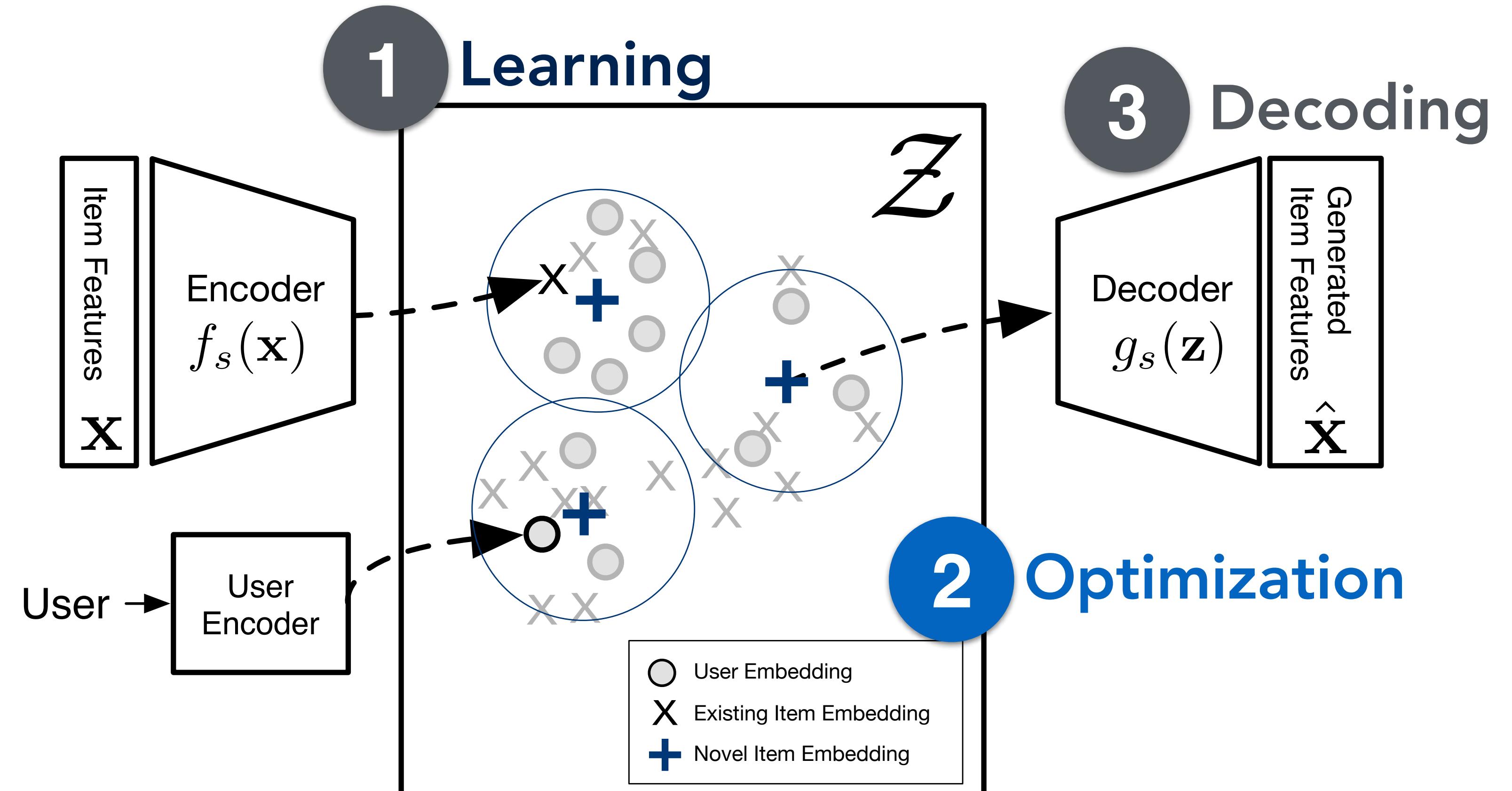


$$\ell(\theta, \phi; d) = \mathbb{E}_{q(\mathbf{z}_i|f_\phi(\mathbf{x}_i))}[\log p(r_{ui}|\mathbf{z}_u, \mathbf{z}_i)] + \mathbb{E}_{q(\mathbf{z}_i|f_\phi(\mathbf{x}_i))}[\log p(\mathbf{x}_i|g_\theta(\mathbf{z}_i))] - \mathbb{D}_{\text{KL}}[q(\mathbf{z}_i|f_\phi(\mathbf{x}_i))||p(\mathbf{z}_i)]$$

Rating prediction

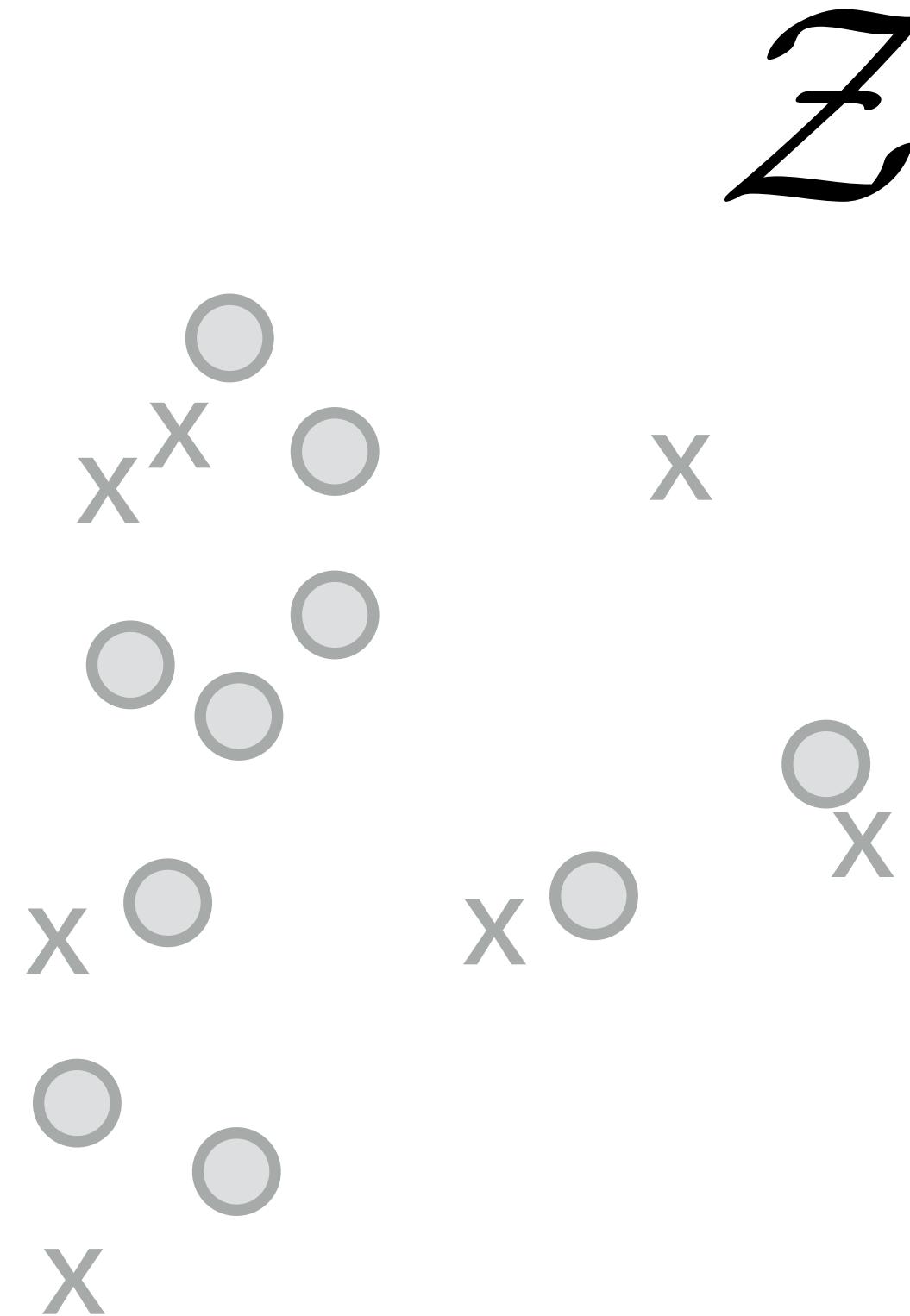
Item reconstruction

Prior Penalty



Greedy Maximum Coverage

● User
X Existing Item



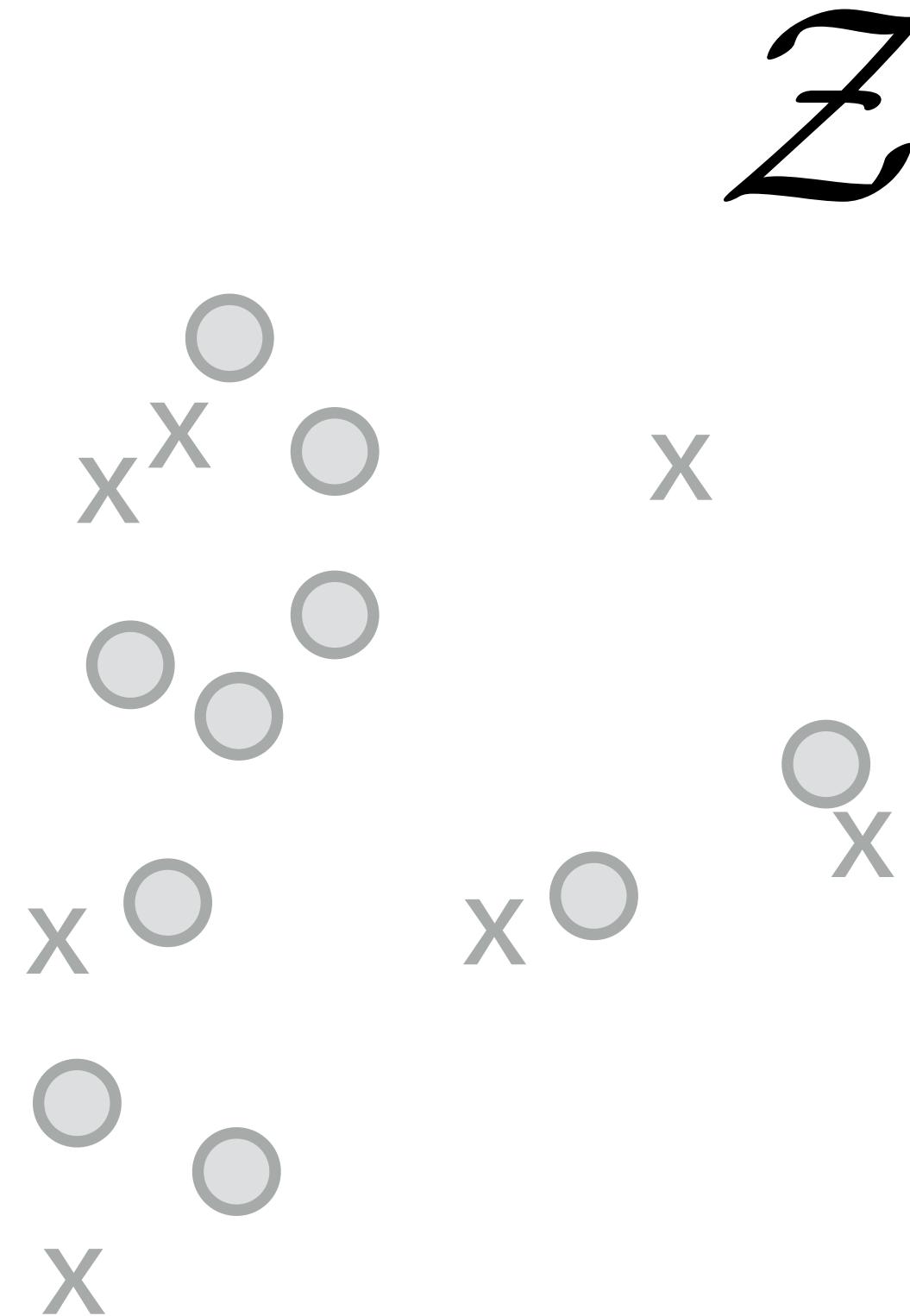
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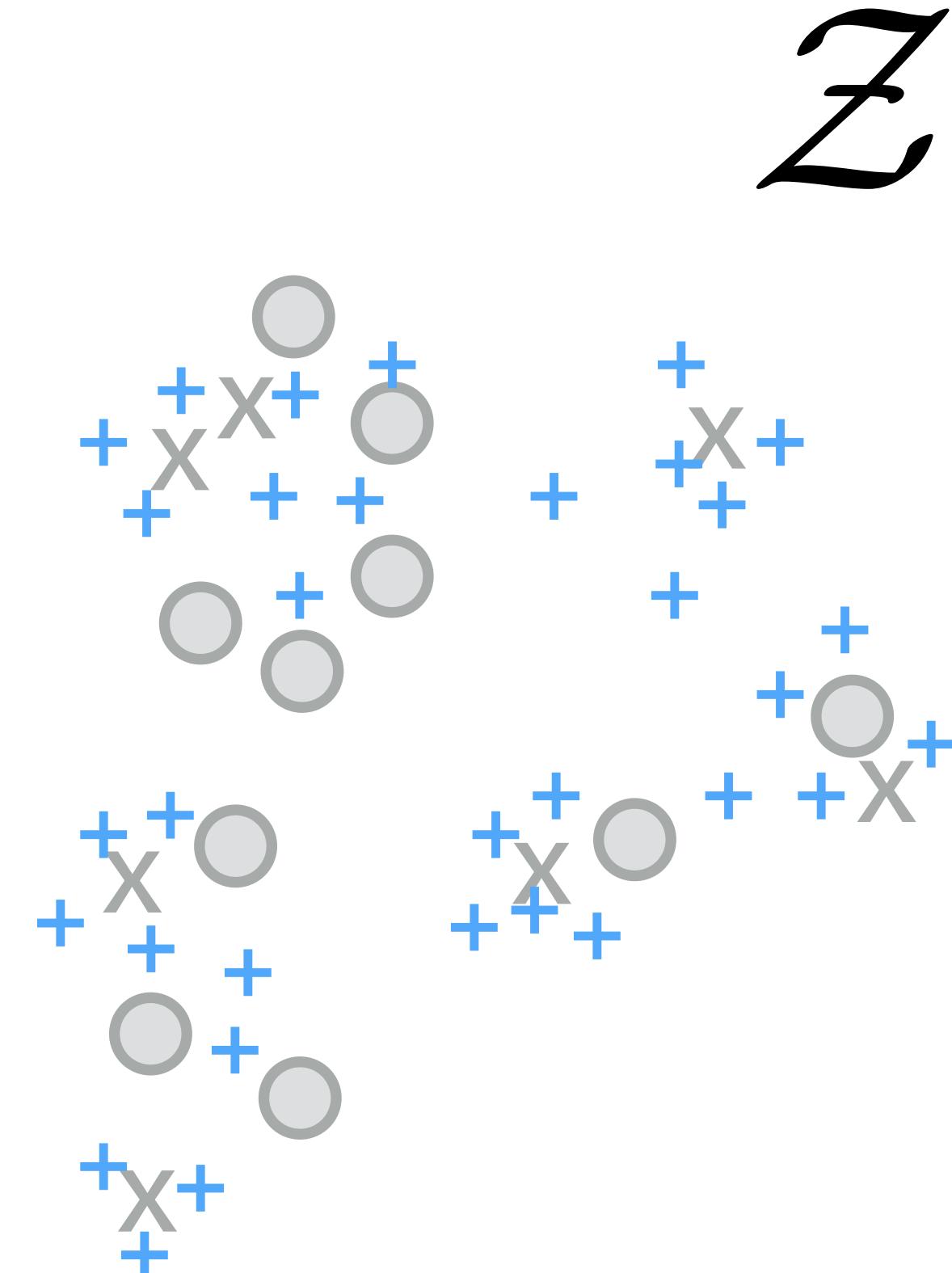
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Greedy Maximum Coverage

- User
- ✗ Existing Item
- + Candidate Novel Item


 \mathcal{Z}

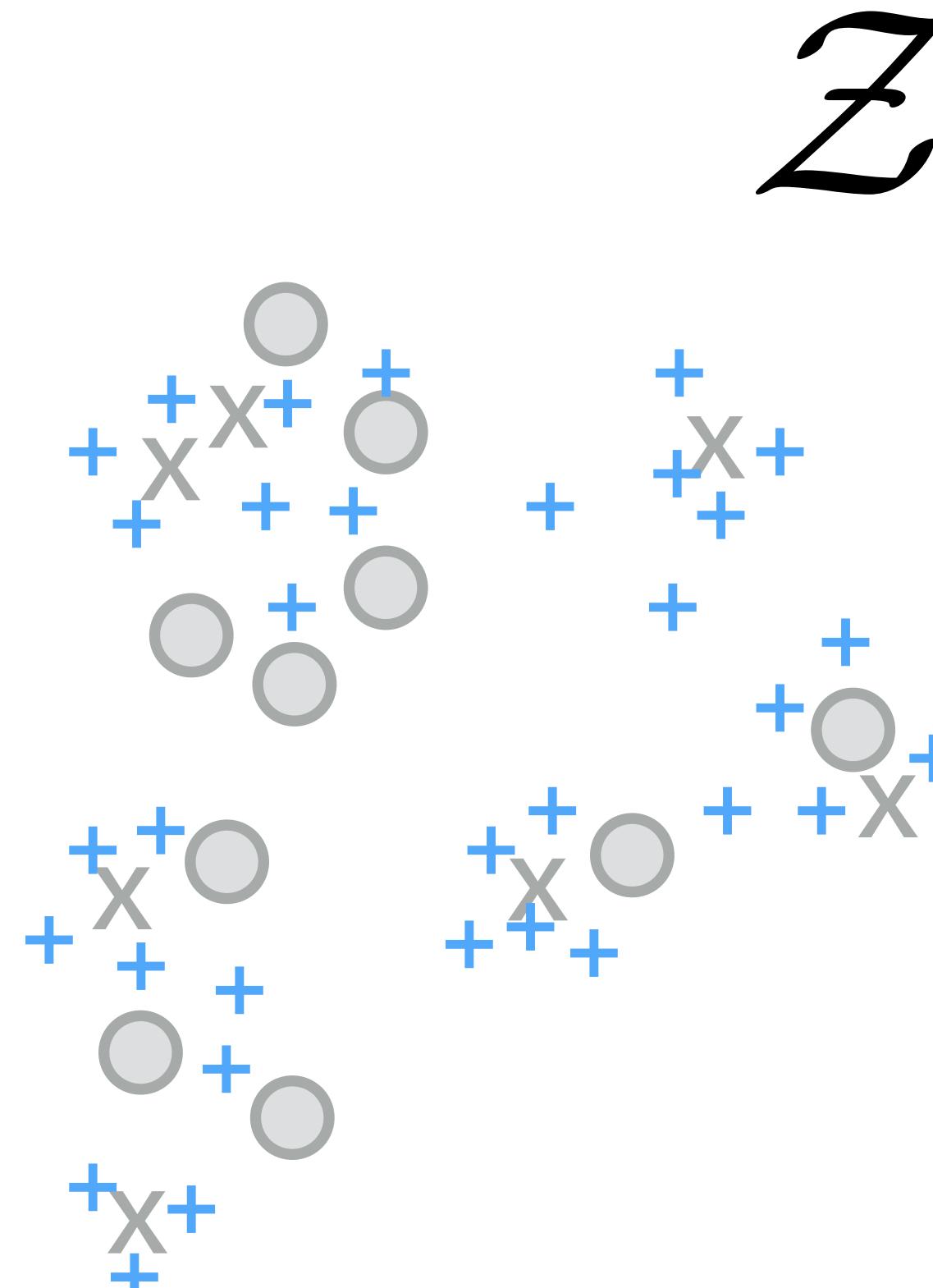
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- Submodular [Nemhauser, Wolsey, Fisher, 1978]
- Achieves $1 - \frac{1}{e}$ approximation ratio
- best polynomial time algorithm unless P = NP

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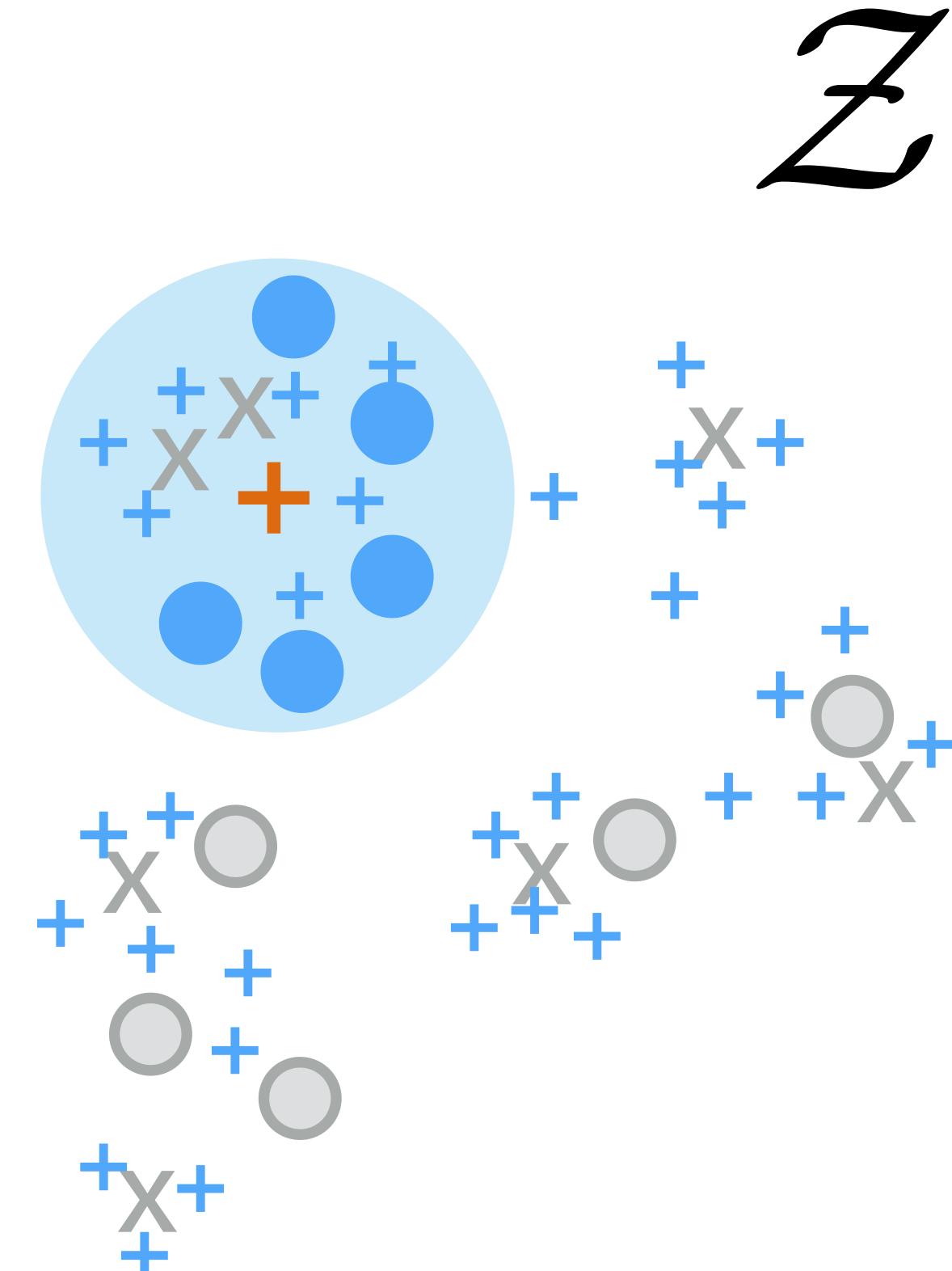
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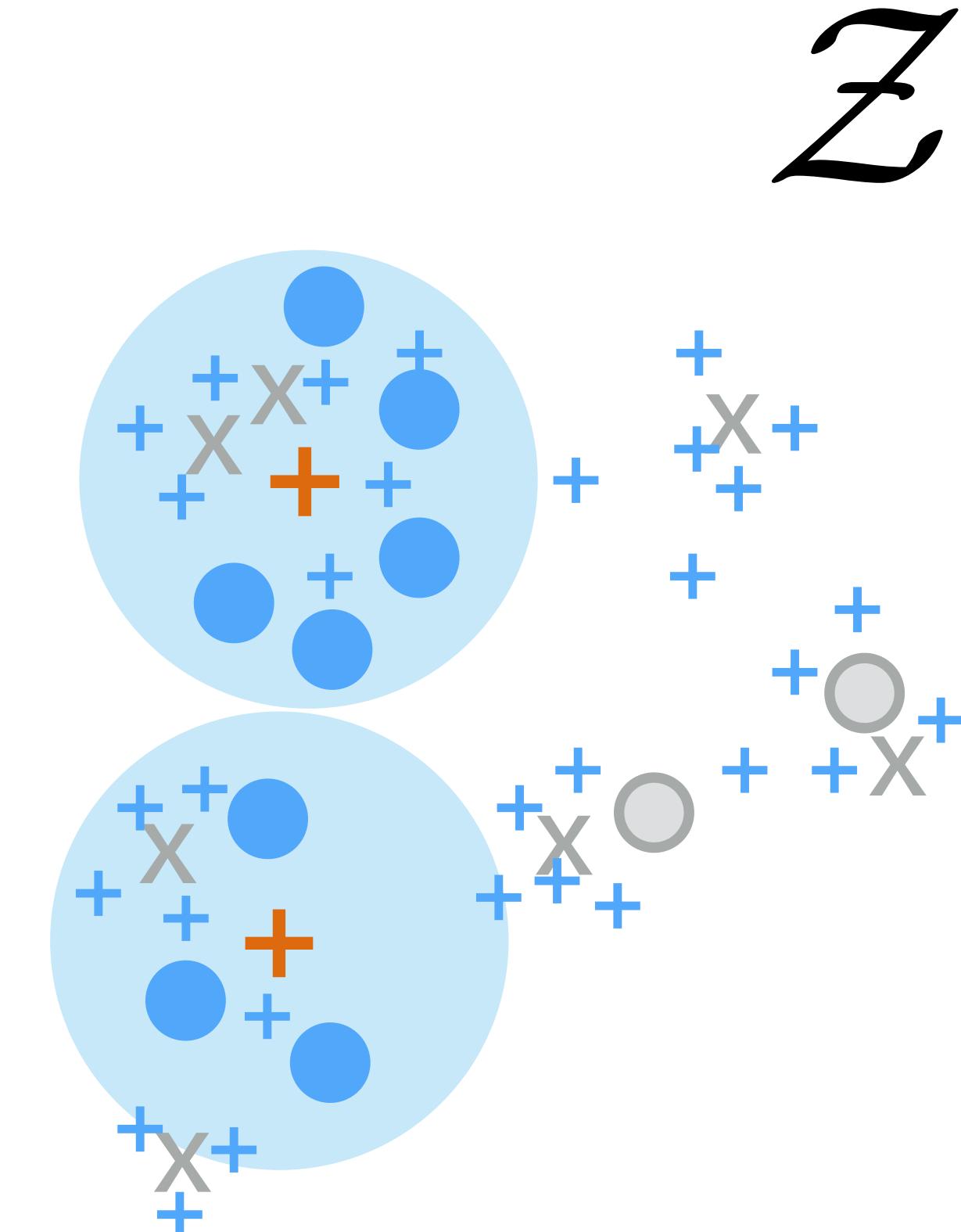
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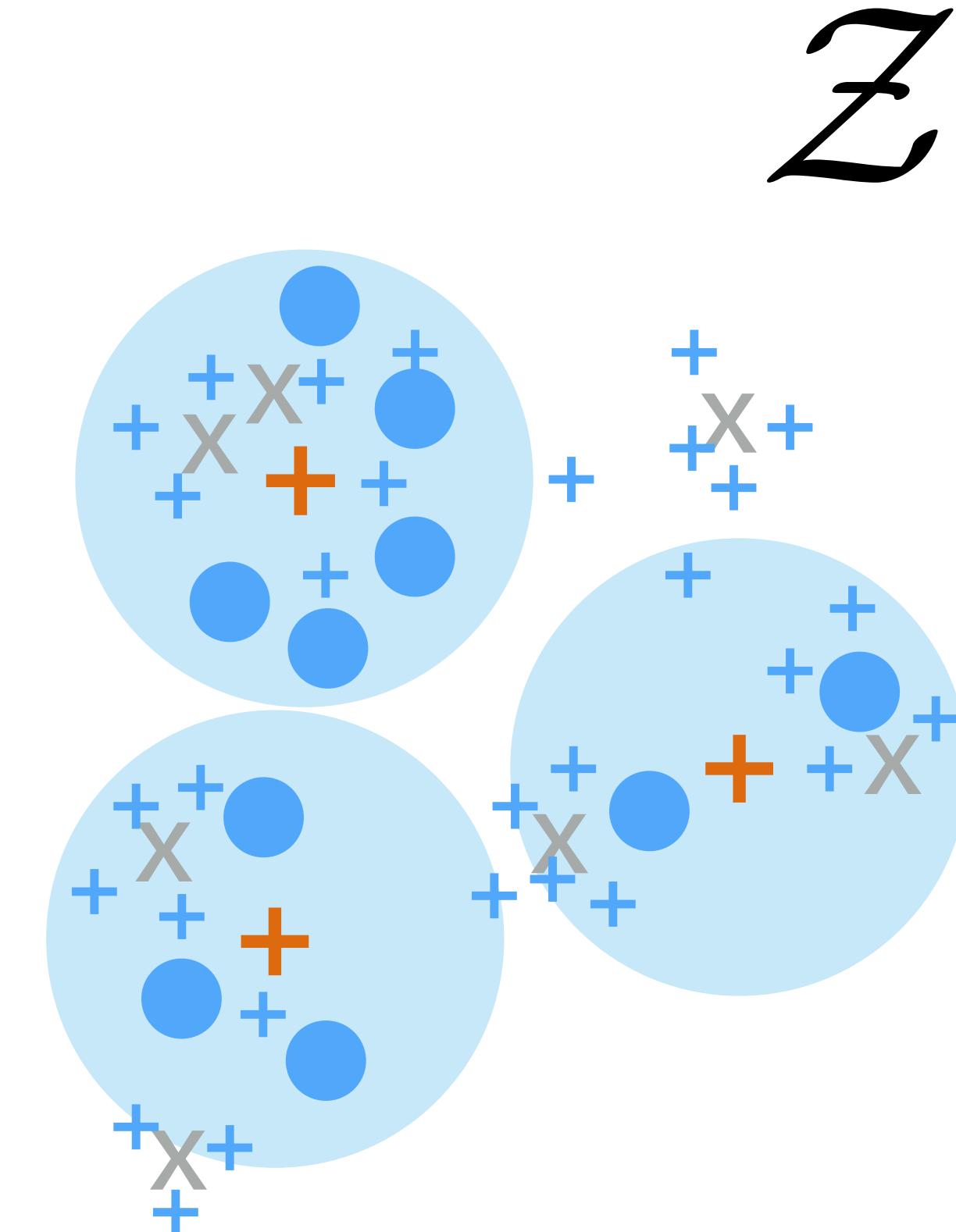
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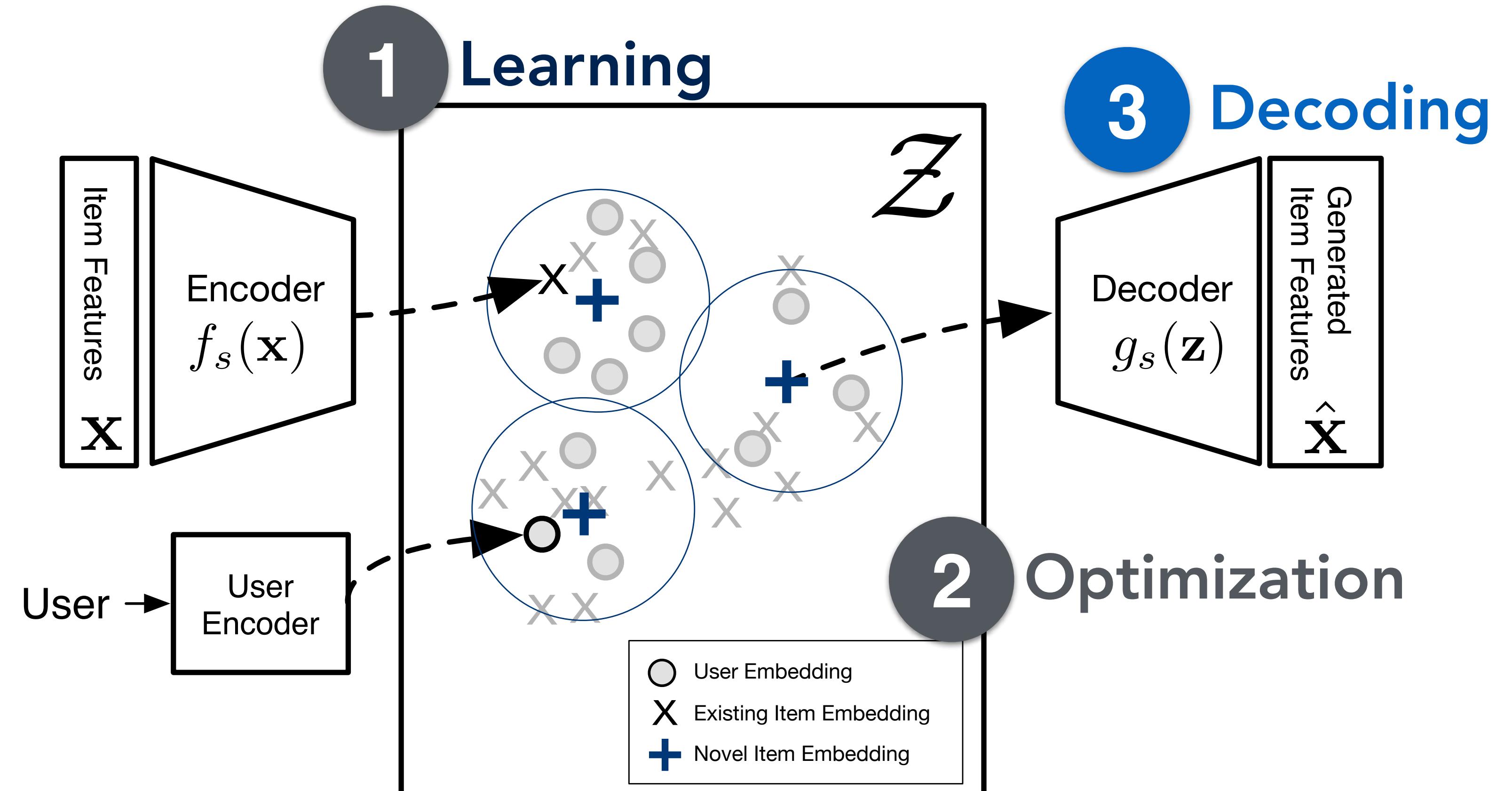


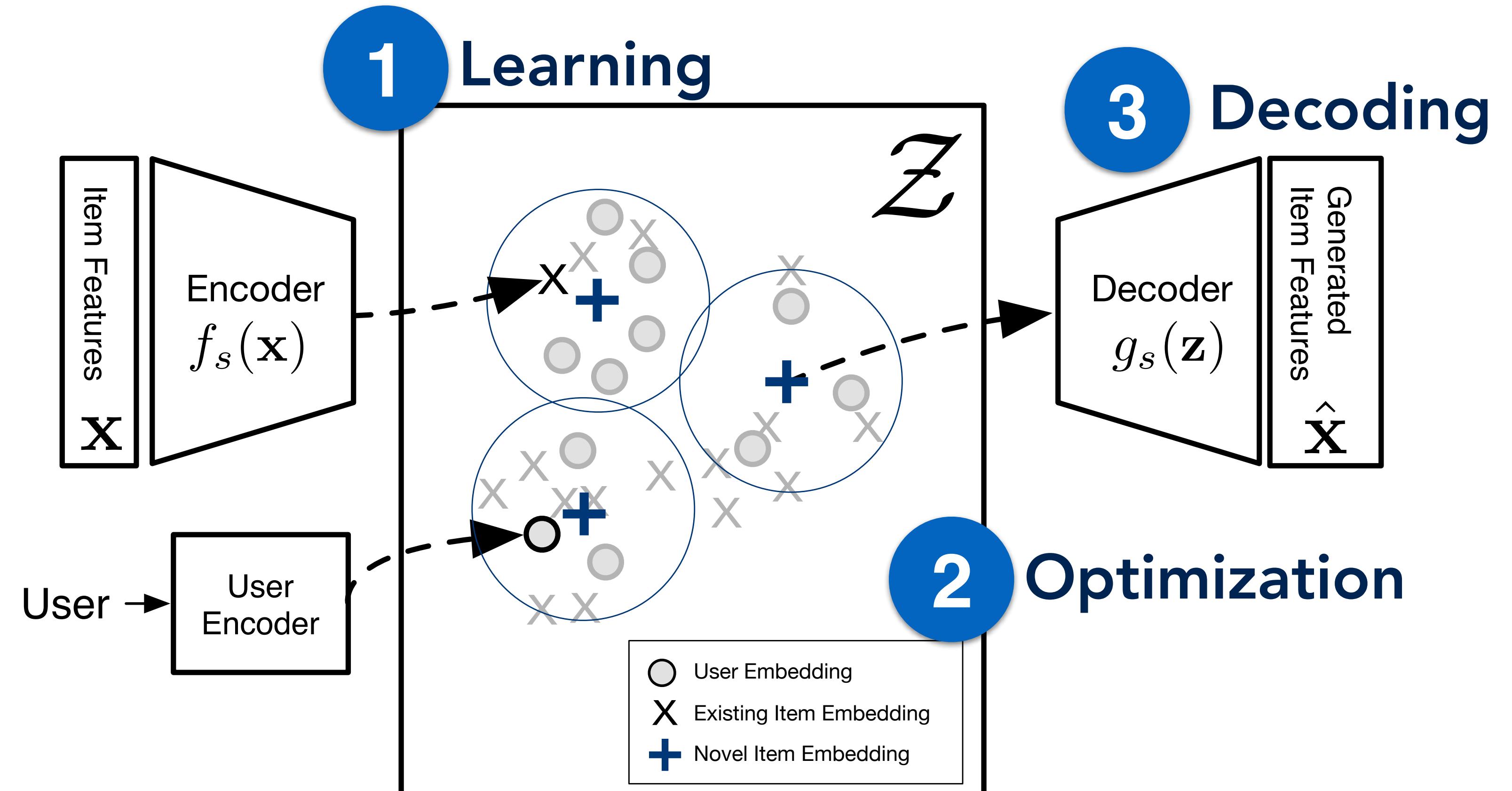
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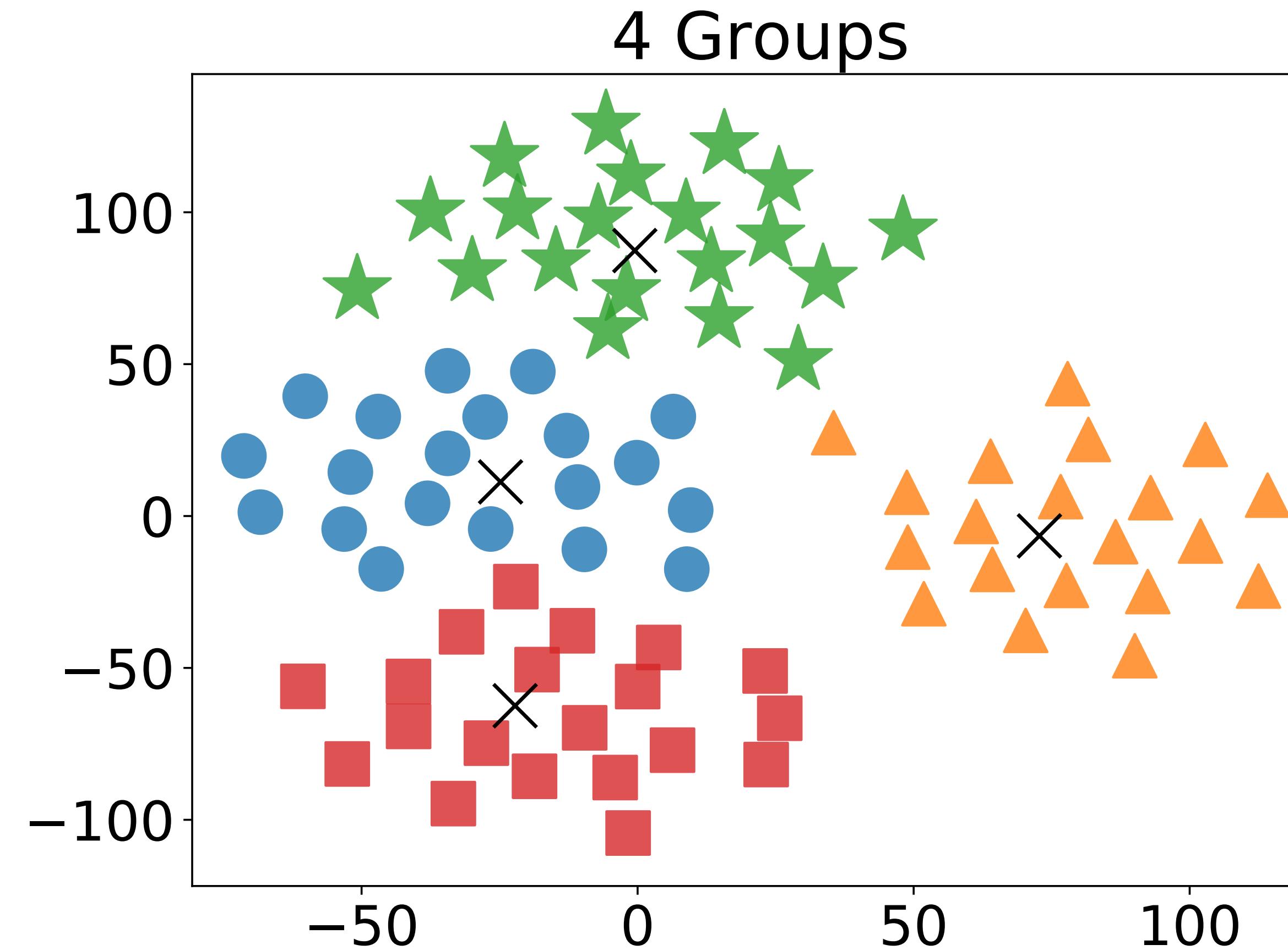
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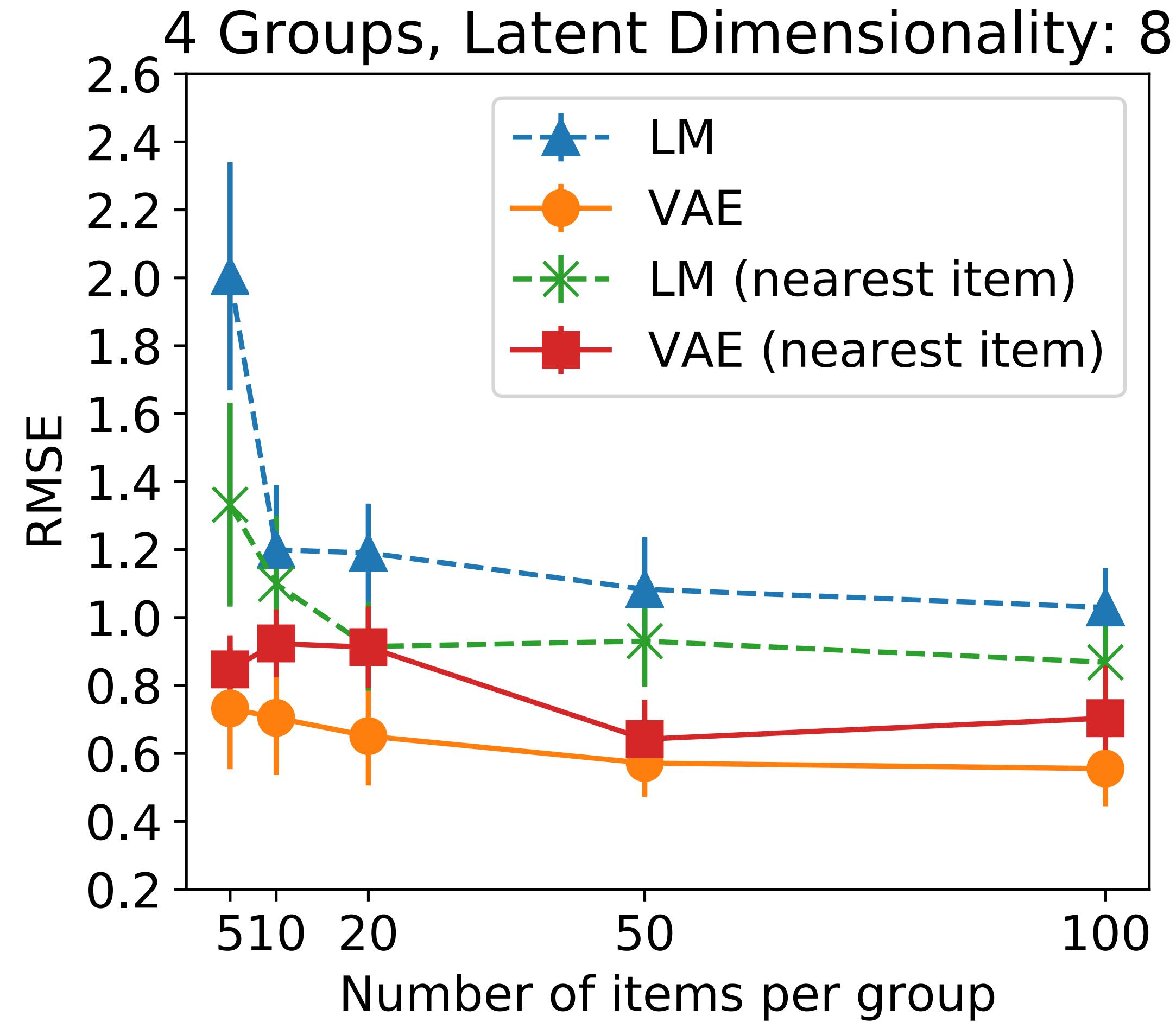


Quantitative Results: Synthetic Data

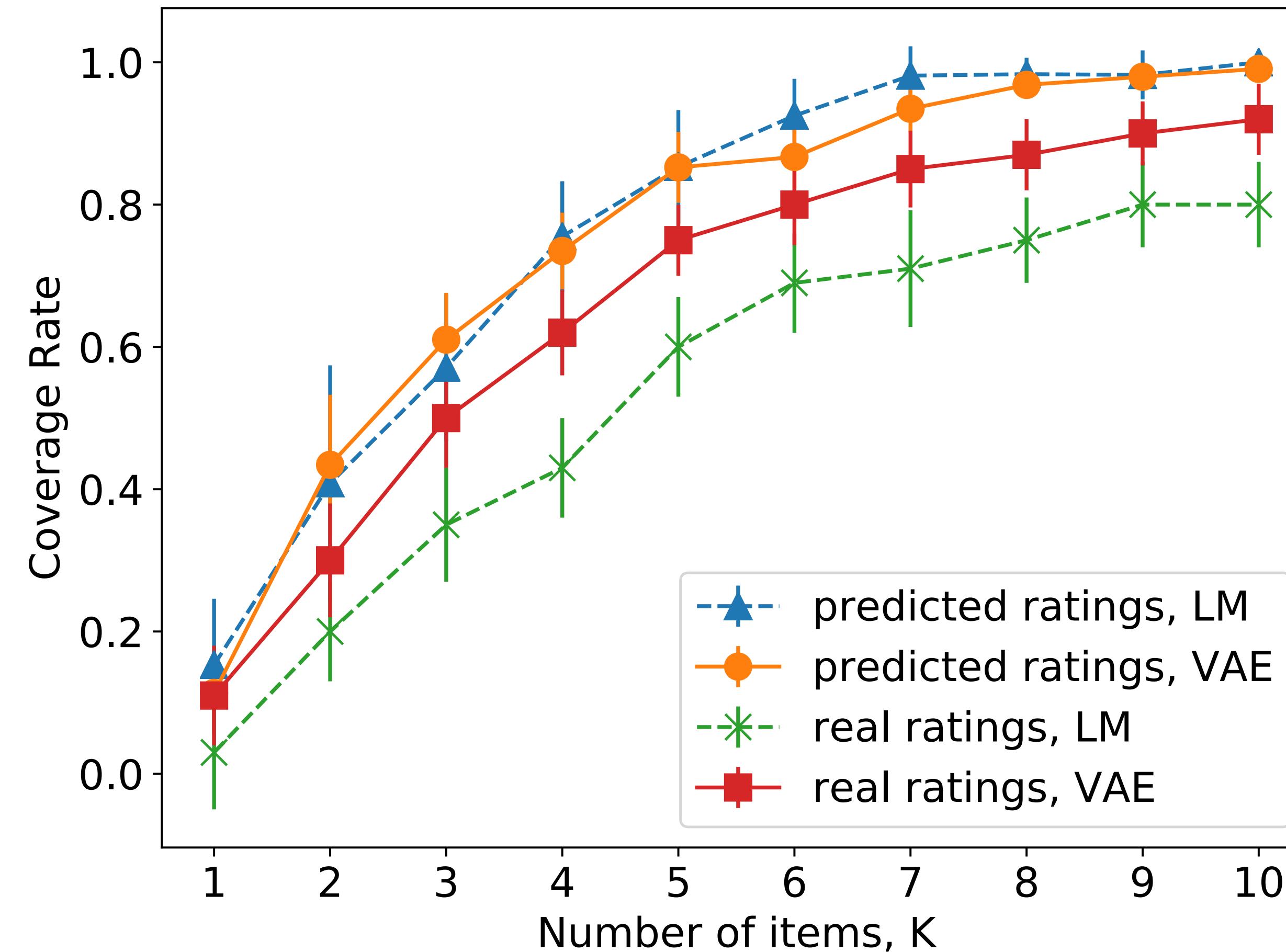


- 20 dimensional items
- Visualized in 2D (via t-SNE)

Quantitative Results: Synthetic Data



Quantitative Results: Synthetic Data



Generated Movie "Genomes"

Generated Movie 1

 PredR(all): 0.87 ± 0.07 , PredR($> \tau$): 0.89 ± 0.05

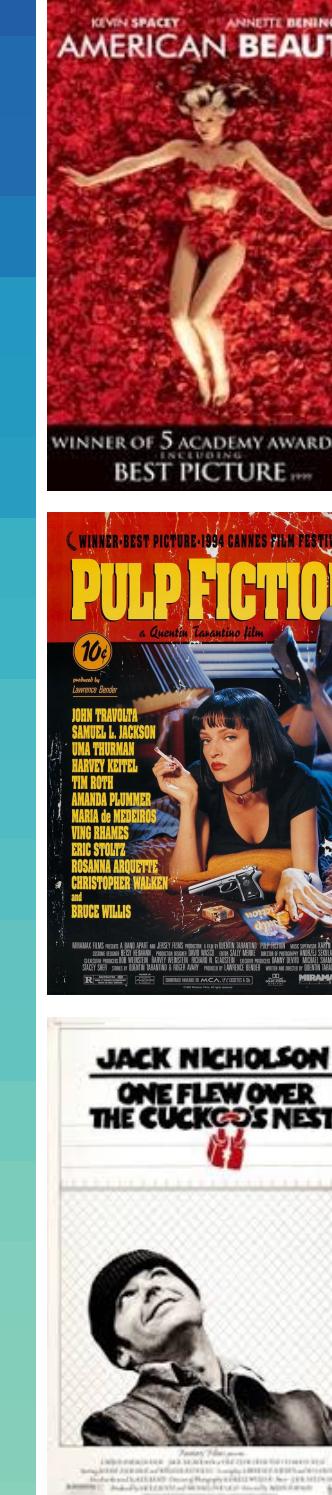
drama	0.84
dramatic	0.83
excellent script	0.83
mentor	0.74
classic	0.73
sentimental	0.71
great ending	0.7
story	0.69
touching	0.67
storytelling	0.66
poignant	0.65
friendship	0.65
intense	0.61
redemption	0.61
culture clash	0.61
narrated	0.6
realistic	0.59
emotional	0.58
social commentary	0.58
quotable	0.58



Generated Movie 2

 PredR(all): 0.84 ± 0.1 , PredR($> \tau$): 0.89 ± 0.05

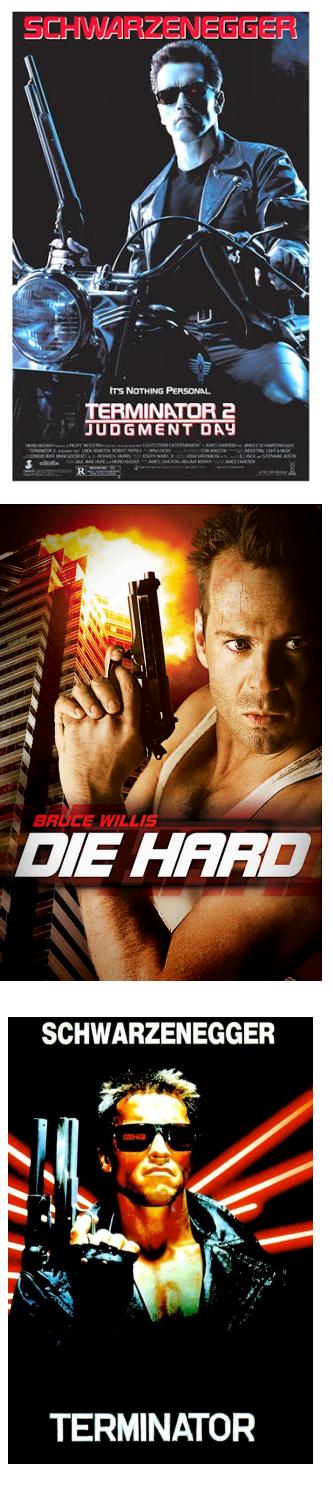
storytelling	0.87
social commentary	0.85
excellent script	0.85
narrated	0.83
dark humor	0.79
drama	0.79
loneliness	0.78
great ending	0.75
reflective	0.74
violence	0.73
quotable	0.72
complex	0.72
criterion	0.7
bleak	0.7
mentor	0.69
visually appealing	0.68
dramatic	0.67
clever	0.67
thought-provoking	0.67
weird	0.67



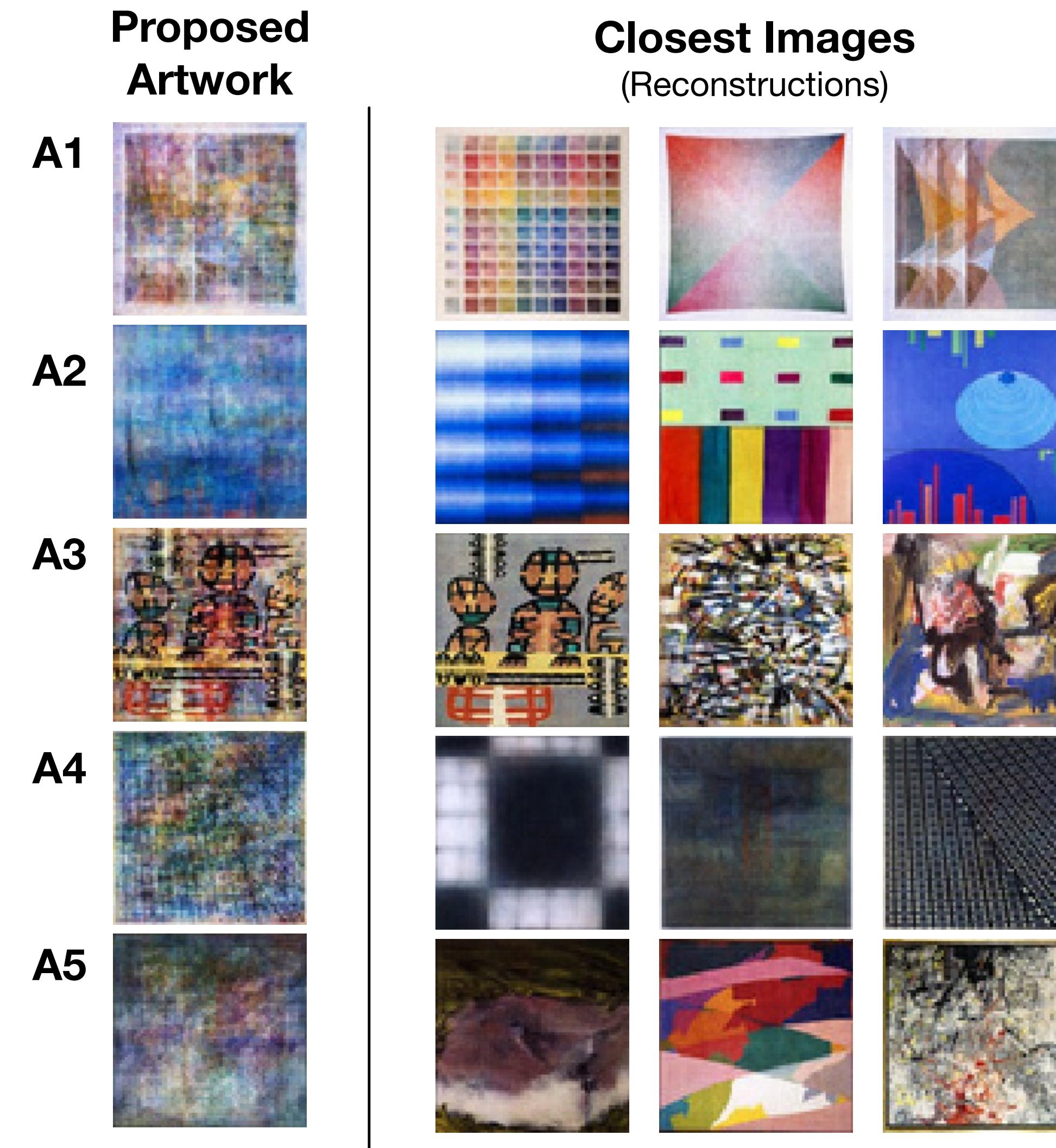
Generated Movie 3

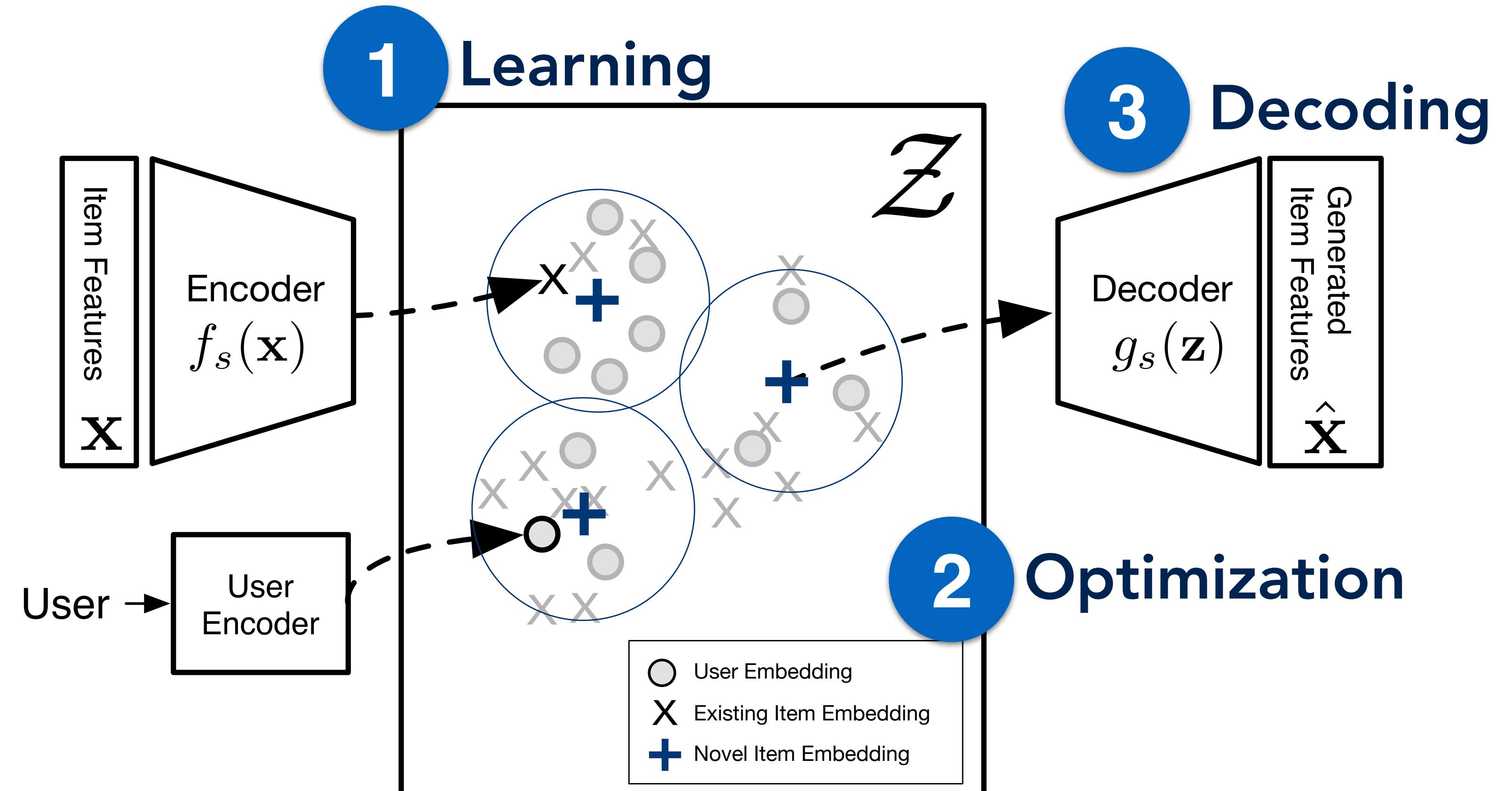
 PredR(all): 0.72 ± 0.16 , PredR($> \tau$): 0.88 ± 0.05

action	0.97
special effects	0.93
franchise	0.84
big budget	0.81
violence	0.81
sci-fi	0.79
story	0.78
tense	0.78
arnold	0.77
fast paced	0.76
fighting	0.76
visceral	0.74
future	0.74
adventure	0.73
intense	0.73
original plot	0.73
effects	0.72
mentor	0.68
suspense	0.68
survival	0.66



Generated Abstract Art





Future Work: What's Next?

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**Alternative Problem
Formalizations**



**Domain-specific
Item Generation**

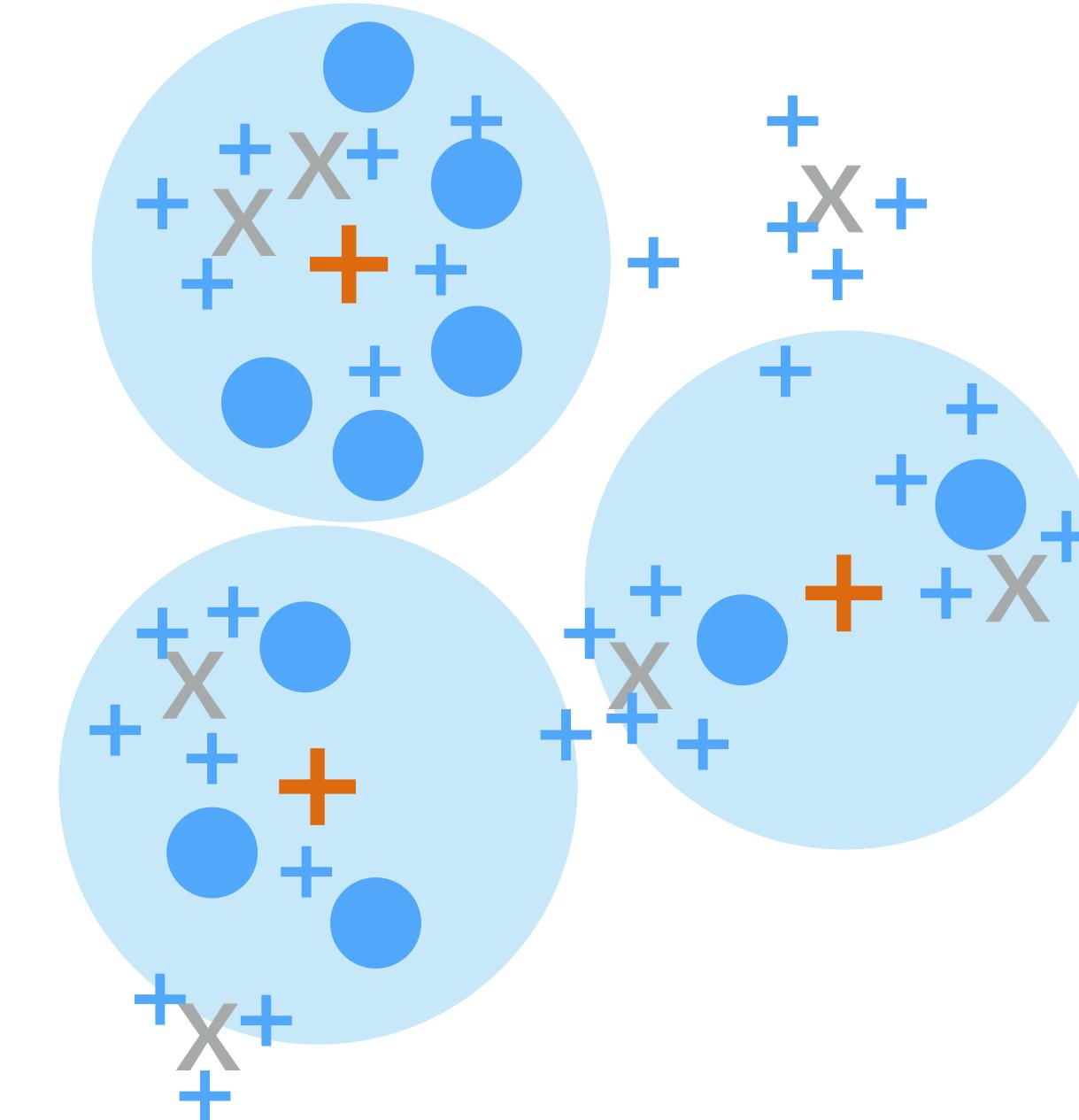


**Collaborative Work with
Human-in-the-loop**



Future Work: What's Next?

Alternative Problem Formalizations



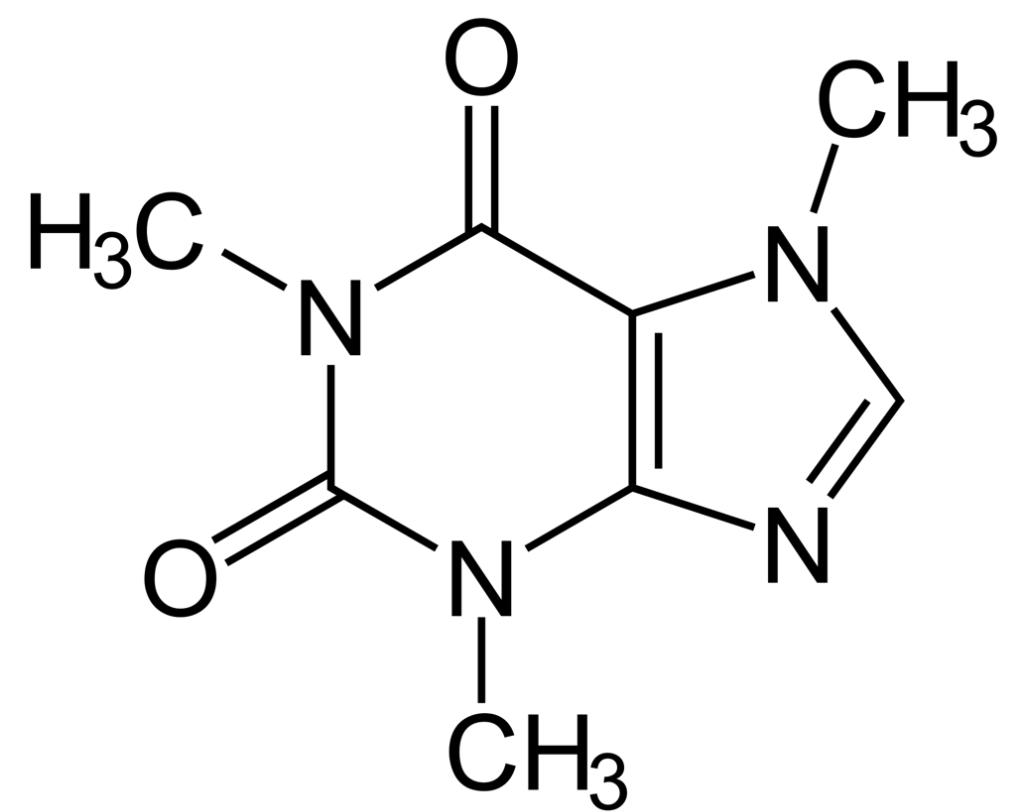
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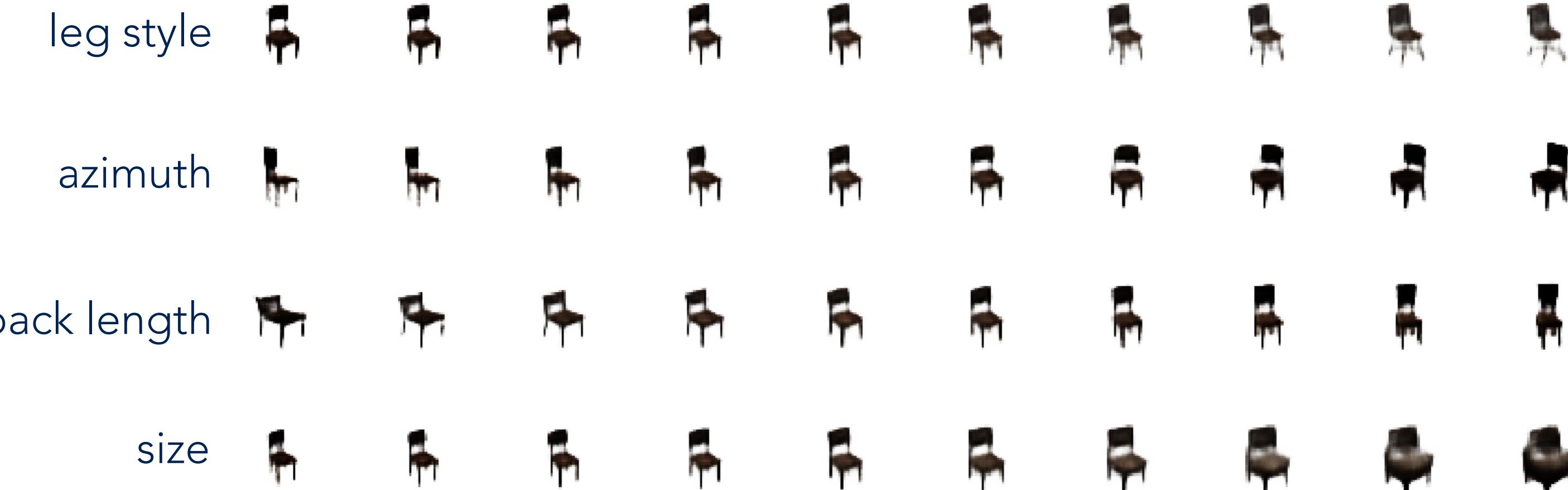


Future Work: What's Next?

**Collaborative Work with
Human-in-the-loop**



Z



[Ansari & Soh, arXiv 2018]

Thank you. Questions?

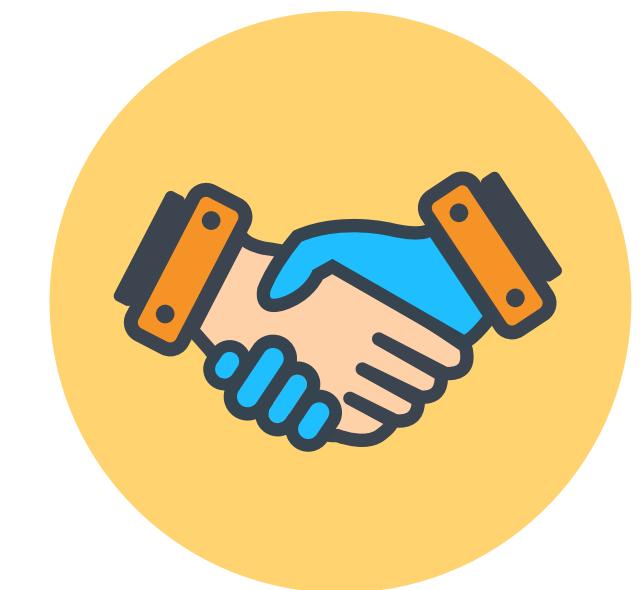
Alternative Problem Formalizations



Domain-specific Item Generation



Collaborative Work with Human-in-the-loop



Generation Meets Recommendation:
Proposing Novel Items for Groups of Users

Thanh Vinh Vo and Harold Soh
{vinhvt, harold}@comp.nus.edu.sg


NUS
National University
of Singapore

If you're in a hurry (TL;DR)

- We address the problem of **recommendation for item makers** instead of consumers: how can we generate a set of **new items** that appeals to a large number of people?
- We present a problem formalization based on **learned latent real-vector spaces**.

Experiments & Results

- Validated model on a 20-dimensional synthetic dataset.
- **Key Question:** Can we recreate the missing items?
- **Key Results:** Yes, to a good degree (RMSE).

