Monte Carlo Tree Search for Algorithm Configuration: MOSAIC

Herilalaina Rakotoarison and Michèle Sebag
TAU

CNRS - INRIA - LRI - Université Paris-Sud









NeurIPS MetaLearning Wshop — Dec. 8, 2018

Monte Carlo Tree Search for Algorithm Configuration: MOSAIC

Herilalaina Rakotoarison and Michèle Sebag

Tackling the Underspecified

CNRS - INRIA - LRI - Université Paris-Sud









NeurIPS MetaLearning Wshop — Dec. 8, 2018

AutoML: Algorithm Selection and Configuration

A mixed optimization problem

Find
$$\lambda^* \in \arg\min_{\lambda \in \Lambda} \mathcal{L}(\lambda, P)$$

with λ a pipeline and $\mathcal L$ the predictive loss on dataset P

Modes

- offline hyper-parameter setting
- online hyper-parameter setting

Approaches

Bayesian optimization: SMAC, Auto-SkLearn, AutoWeka, BHOB
 Hutter et al., 11; Feurer et al. 15; Kotthoff et al. 17; Falkner et al. 18

Evolutionary Computation

Olson et al. 16; Choromanski et al. 18

▶ Bilevel optimization

Franceschi et al. 17, 18

Reinforcement learning

Andrychowicz 16; Drori et al. 18

Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

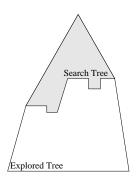
- ► Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

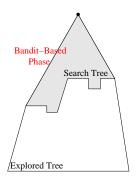
- Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Gaudel, Sebag, 10

Rolet, Teytaud, Sebag, 09

Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

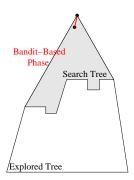
- ► Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

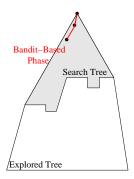
- ► Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

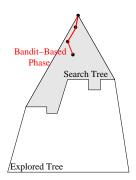
- ▶ Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

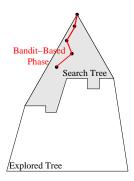
- Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Gaudel, Sebag, 10

Rolet, Teytaud, Sebag, 09

Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

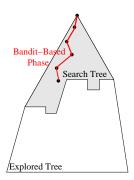
- Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Gaudel, Sebag, 10

Rolet, Teytaud, Sebag, 09

Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

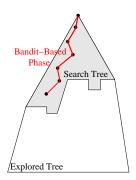
- Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

- Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

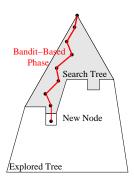
- Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

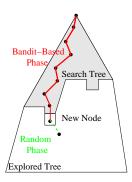
- ▶ Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Rolet, Teytaud, Sebag, 09

Gaudel, Sebag, 10

Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

- ▶ Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - ► Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

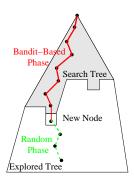
- Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Kocsis & Szepesvári 06, Gelly & Silver 07

Game playing when no good evaluation function and huge search space.

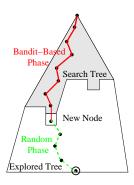
- Upper Confidence Tree (UCT)
 - Gradually grow the search tree
 - Building Blocks
 - Select next action (bandit-based phase)

Auer et al. 02

- Add a node (leaf of the search tree)
- Select next action bis (random phase)
- Compute instant reward
- Update information in visited nodes
- Returned solution
 - Path visited most often

Within learning

Feature selection Active learning



Gaudel, Sebag, 10

Rolet, Teytaud, Sebag, 09

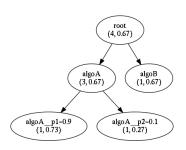
Monte Carlo Tree Search for AutoML

1. Select next action (alg/hyperparameter)

$$\text{select } \arg \max_i \left\{ \mu_i + c \sqrt{\frac{\log N}{n_i}} \right\}$$

with μ_i average reward, n_i number visits, $N = \sum_i n_i$

- Add a node: new alg or hyper-parameter;
- Random phase: complete pipeline with default/random choices.
- 4. Compute reward *v*: predictive accuracy of pipeline
- 5. Use v to **update** μ_i , increment n_i in all visited nodes



Mosaic: MCTS for AutoML

Overview

- ► Search space: { Preprocessing algs } × { Algorithms }
- Fixed sequence of choices:
 - 1. Preprocessing alg
 - 2. hyper-parameters of pre-processing alg
 - 3. Algorithm
 - 4. hyper-parameters of Alg.

PCA, random proj,...

SVM, RF, ...

C, ϵ ,...

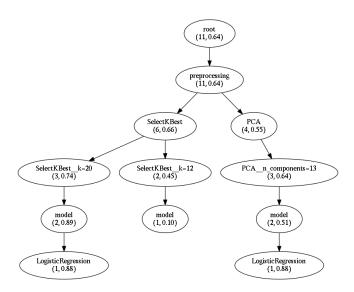
Key features

- CPU management (every Δt, kills unpromising pipelines; increases evaluation resources for others)
- ► Sample continuous hyperparameters: Progressive widening

Gelly Silver 07

Increase number of sampled values like $\left|\sqrt{N}\right|$

A MOSAIC Tree



Search space

	Methods	Parameters
Preprocessing	PCA	n_components
	SelectKBest	k, score_func
	Gaussian Random Projection	n_components, eps
	No preprocessing	-
Algorithm	Logistic regression	C, penalty, solver
	SGD Classifier	learning rate, penalty,
	SGD Classifier	alpha, l1 ratio, loss
	KNN classifier	K, metric, weights
	XGBoost classifier	learning rate, max depth, gamma, subsample, regularization
	LDA	n_components,learning decay
	Random forest	criterion, max features, max depth, bootstrap,
		min sample split

Experiments and Results

AutoML Challenge PAKDD 2018

- Binary classification (Final phase)
- ▶ 10 or 20 minutes time budget for each dataset
- ► Metric: balanced accuracy

	Set 1	Set 2	Set 3	Set 4	Set 5
aad_freiburg	0.5533	0.2839	0.3932	0.2635	0.6766
mosaic	0.5382	0.3161	0.3376	0.3182	0.6317
narnars0	0.5418	0.2894	0.3665	0.2005	0.6922
W wang	0.5655	0.4851	0.2829	-0.0886	0.6840

Final test phase: mosaic ranked second w.r.t. average rank.

Experiment 2: extended pre-processing search space

Methods	Parameters
PCA	n_components, whiten, svd_solver, tol, iterated_power
KernelPCA	n_components, kernel, gamma, degree, coef0, alpha, eigen_solver, tol, max_iter
FastICA	n_components, algorithm, max_iter, tol, whiten, fun
Identity	-
IncrementalPCA	n_components, whiten, batch_size
SelectKBest	score_func, k
SelectPercentile	score_func, percentile
LinearSVC Pre-processing	C, class_weight, max_iter
	n_estimators, criterion, max_depth,
ExtraTreesClassifier	min_samples_split, min_samples_leaf,
Pre-processing	min_weight_fraction_leaf, max_features,
	max_leaf_nodes, class_weight
FeatureAgglomeration	n_clusters, affinity, linkage
PolynomialFeatures	degree
RBFSampler	gamma, n_components
	n_components, max_depth, min_samples_split,
RandomTreesEmbedding	min_samples_leaf, min_weight_fraction_leaf, max_leaf_nodes,
	min impurity decrease

Experiment 2: extended algorithm search space

Algorithms	Parameters		
LinearDiscriminantAnalysis	solver, shrinkage		
QuadraticDiscriminantAnalysis	reg_param		
DummyClassifier	-		
AdaBoostClassifier	base_estimator, n_estimators,		
	learning_rate, algorithm		
	n_estimators, criterion, max_depth,		
ExtraTreesClassifier	min_samples_split, min_samples_leaf,		
Extra freesClassifier	min_weight_fraction_leaf, max_features,		
	max_leaf_nodes, class_weight		
	n_estimators, criterion, min_samples_split,		
RandomForestClassifier	min_samples_leaf, min_weight_fraction_leaf,		
RandomForestClassifier	max_features, max_leaf_nodes,		
	class_weight, bootstrap		
	loss, learning_rate, n_estimators,		
GradientBoostingClassifier	max_depth, criterion, min_samples_split,		
GradientBoostingClassiner	min_samples_leaf, min_weight_fraction_leaf,		
	subsample, max_features, max_leaf_nodes		
	learning rate, penalty,		
SGD Classifier	alpha, l1 ratio, loss, epsilon,		
	eta0, power_t, class_weight, max_iter		

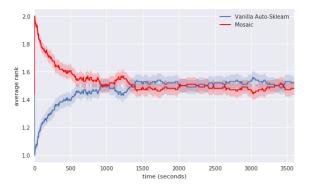
Experiment 2: extended algorithm search space, foll.

Algorithms	Parameters		
Perceptron	penalty, alpha, max_iter, tol, shuffle, eta0		
RidgeClassifier	alpha, max_iter, class_weight, solver		
PassiveAggressiveClassifier	C, max_iter, tol, loss, class_weight		
KNeighborsClassifier	n_neighbors, weights, algorithm, leaf_size, p, metric		
-	hidden_layer_sizes, activation, solver,		
	alpha, batch_size, learning_rate,		
MLPClassifier	learning_rate_init, power_t, max_iter,		
WILI Classifier	shuffle, warm_start, momentum,		
	nesterovs_momentum, early_stopping,		
	validation_fraction, beta_1, beta_2, epsilon		
SVC	C, max_iter, tol, loss, class_weight,		
300	kernel, degree, gamma, coef0		
	criterion, splitter, max_depth, min_samples_split,		
DecisionTreeClassifier	min_samples_leaf, min_weight_fraction_leaf,		
Decision free classifier	max_features, max_leaf_nodes,		
	min_impurity_decrease, class_weight		
	criterion, splitter, max_depth, min_samples_split,		
ExtraTreeClassifier	min_samples_leaf, min_weight_fraction_leaf,		
Latia HeeClassiller	max_features, max_leaf_nodes,		
	min_impurity_decrease, class_weight		

Experiment 2

On 133 datasets from the OpenML repository 1 hour per (dataset, run); 10 runs per dataset.

Vanschoren et al. 14



Average rank (lower is better) of MOSAIC and Vanilla Auto-Sklearn across 102 datasets (Datasets on which the performance of both methods differs statistically according to Mann-Whitney rank test with p=0.05).

Discussion

Monte Carlo Tree Search for Algorithm Configuration

▶ Proof of concept

Limitations

- ▶ Order of hyper-parameters
- ▶ Time allocation

Perspectives

Short term

- ► Refine initialization
- Extend to constrained satisfaction

Medium term

- ▶ Learn value of parameters across datasets
- ▶ Improving the sampling of continuous hyperparameter values

Long term

Learning Meta-Features: a (the) key Meta-Learning task.