Message Passing Algorithms for Dirichlet Diffusion Trees

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Abstract

We demonstrate efficient approximate inference for the Dirichlet Diffusion Tree (Neal, 2003), a Bayesian nonparametric prior over tree structures. Although DDTs provide a powerful and elegant approach for modeling hierarchies they haven’t seen much use to date. One problem is the computational cost of MCMC inference. We provide the first deterministic approximate inference methods for DDT models and show excellent performance compared to the MCMC alternative. We present message passing algorithms to approximate the Bayesian model evidence for a specific tree. This is used to drive sequential tree building and greedy search to find optimal tree structures, corresponding to hierarchical clusterings of the data. We demonstrate appropriate observation models for continuous and binary data. The empirical performance of our method is very close to the computationally expensive MCMC alternative on a density estimation problem, and significantly outperforms kernel density estimators.

1. Introduction

Tree structures play an important role in machine learning and statistics. Learning a tree structure over data points gives a straightforward picture of how objects of interest are related. Trees are easily interpreted and intuitive to understand. Sometimes we may know that there is a true underlying hierarchy: for example species in the tree of life or duplicates of genes in the human genome, known as paralogs. Typical mixture models, such as Dirichlet Process mixture models, have independent parameters for each component. In many situations we might expect that certain clusters are similar, for example are sub-groups of some large group. By learning this hierarchical similarity structure, the model can share statistical strength between components to make better estimates of parameters using less data.

Traditionally, a family of methods known as hierarchical clustering is used to learn tree structures. Classical hierarchical clustering algorithms employ a bottom-up “agglomerative” approach (Duda et al., 2001): start with a “hierarchy” of one datapoint and iteratively add the closest datapoint in some metric into the hierarchy. The output of these algorithms is usually a binary tree or dendrogram. Although these algorithms are straightforward to implement, both the ad-hoc method and the distance metric hide the statistical assumptions being made.

Two solutions to this problem have recently been proposed. In Heller & Ghahramani the bottom-up agglomerative approach is kept but a principled probabilistic model is used to find subtrees of the hierarchy. Bayesian evidence is then used as the metric to decide which node to incorporate in the tree. Although fast, the lack of a generative process prohibits modeling uncertainty over tree structures. A different line of work (Williams, 2000; Neal, 2003; Teh et al., 2008; Blei et al., 2010; Roy et al., 2006) starts from a generative probabilistic model for both the tree structure and the data. Bayesian inference machinery can then be used to compute posterior distributions on both the internal nodes of the tree as well as the tree structures themselves.
An advantage of the generative probabilistic models for trees is that they can be used as a building block for other latent variable models (Rai & Daumé III, 2008). We could use this technique to build topic models with hierarchies on the topics, or hidden Markov models where the states are hierarchically related. Greedy agglomerative approaches can only cluster latent variables after inference has been done and hence they cannot be used in a principled way to aid inference in the latent variable model.

In this work we use the Dirichlet Diffusion Tree (DDT) introduced in Neal (2003), and reviewed in Section 2. This simple yet powerful generative model specifies a distribution on binary trees with multivariate Gaussian distributed variables at the leaves. The DDT is a Bayesian nonparametric prior, and is a generalization of Dirichlet Process mixture models (Rasmussen, 2000). The DDT can be thought of as providing a very flexible density model, since the hierarchical structure is able to effectively fit non-Gaussian distributions. Indeed, in Adams et al. (2008) the DDT was shown to significantly outperform a Dirichlet Process mixture model in terms of predictive performance, and in fact slightly outperformed the Gaussian Process Density Sampler. The DDT is thus both a mathematically elegant nonparametric distribution over hierarchies and provides state-of-the-art density estimation performance.

Our algorithms use the message passing framework (Kschischang et al., 2001; Minka, 2005). For many models message passing has been shown to significantly outperform sampling methods in terms of speed-accuracy trade-off. However, general α-divergence (Minka, 2005) based message passing is not guaranteed to converge, which motivates our second, guaranteed convergent, algorithm which uses message passing within EM (Kim & Ghahramani, 2006).

The contributions of this paper are as follows. We derive and demonstrate full message passing (Section 3.1) and message passing within EM algorithms (Section 3.2) to approximate the model evidence for a specific tree, including integrating over hyperparameters (Section 3.3). We show how the resulting approximate model evidence can be used to drive greedy search over tree structures (Section 3.4). We demonstrate that it is straightforward to connect different observation models to this module to model different data types, using binary vectors as an example. Finally we present experiments using the DDT and our approximate inference scheme in Section 4.

2. The Dirichlet Diffusion Tree

The Dirichlet Diffusion Tree was introduced in Neal (2003) as a top-down generative model for trees over $N$ datapoints $x_1, x_2, \ldots, x_N \in \mathcal{R}^p$. The dataset is generated sequentially with each datapoint $x_i$ following the path of a Brownian motion for unit time. We overload our notation by referring to the position of each datapoint at time $t$ as $x_i(t)$ and define $x_i(1) = x_i$.

The first datapoint starts at time 0 at the origin in a $D$-dimensional Euclidean space and follows a Brownian motion with variance $\sigma^2$ until time 1. If datapoint 1 is at position $x_1(t)$ at time $t$, the point will reach position $x_1(t + dt) = x_1(t) + \text{Normal}(0, \sigma^2dt)$ at time $t + dt$. It can easily be shown that $x_1(t) \sim \text{Normal}(0, \sigma^2t)$. The second point $x_2$ in the dataset also starts at the origin and initially follows the path of $x_1$. The path of $x_2$ will diverge from that of $x_1$ at some time $T_2$ (controlled by the “divergence function” $a(t)$) after which $x_2$ follows a Brownian motion independent of $x_1(t)$ until $t = 1$.

The generative process for datapoint $i$ is as follows. Initially $x_i(t)$ follows the path of the previous datapoints. If $x_i$ does not diverge before reaching a previous branching point, the previous branches are chosen with probability proportional to how many times each branch has been followed before. This reinforcement scheme is similar to the Chinese restaurant process (Aldous, 1985). If at time $t$ the path for datapoint $i$ has not yet diverged, it will diverge in the next infinitesimal time step $dt$ with probability $a(t)dt/m$, where $m$ is the number of datapoints that have previously followed the current path. The division by $m$ is another reinforcing aspect of the DDT: the more datapoints follow a particular branch, the more likely subsequent datapoints will not diverge off this branch.

For the purpose of this paper we use the divergence function $a(t) = \frac{c}{t}$, with “smoothness” parameter $c > 0$. Larger values $c > 1$ give smoother densities because divergences typically occur earlier, resulting in less dependence between the datapoints. Smaller values $c < 1$ give rougher more “clumpy” densities with more local structure since divergence typically occurs later, closer to $t = 1$. We refer to Neal (2001) for further discussion of the properties of this and other divergence functions. Figure 1 illustrates the diffusion tree process for a dataset with $N = 4$ datapoints.

Before we describe the functional form of the DDT prior we will need two results. First, the probability that a new path does not diverge between times $s < t$ on a segment that has been followed $m$ times by previous data-points can be written as

$$P(\text{not diverging}) = \exp \left[ (A(s) - A(t))/m \right],$$
This expression factorizes into a term for $t$ where happening is not be a contiguous segment. The probability of this paths diverged before time $t$. By exchangeability we can assume that it was the second path that went through $x_b$, except the first and second, had to choose to follow the left or right branch. Again, by exchangeability, we can assume that all $l(b) - 1$ paths took the left branch first, then all $r(b) - 1$ paths chose the right branch. The probability of this happening is

$$P([ab]) = \frac{(l(b) - 1)!(r(b) - 1)!}{m(b)!}$$

Finally, we include a term for the diffusion locations:

$$P(x_b | x_a, t_a, t_b) = \text{Normal}(x_b; x_a, \sigma^2(t_b - t_a))$$

The full joint probability for the DDT is now a product of terms for each segment

$$P(x, t, T) = \prod_{[ab] \in S(T)} P(x_b | x_a, t_a, t_b)P(t_b | [ab], t_a)P([ab])$$

### 3. Approximate Inference for the DDT

We assume that the likelihood can be written as a product of conditional probabilities for each of the leaves $x_n$: $\prod_n P(y_n | x_n)$ where $y_n$ is observed data. Our aim is to calculate the posterior distribution

$$P(x, t, T | y) = \frac{P(y, x, t, T)}{\sum_T \int P(y, x, t, T) dx dt}$$

Unfortunately, this integral is analytically intractable. Our solution is to use message passing or message passing within EM to approximate the marginal likelihood for a given tree structure: $P(y | T) = \int P(y, x, t | T) dx dt$. We use this approximate marginal likelihood to drive tree building/search algorithm to find a weighted set of $K$-best trees.

#### 3.1. Message passing algorithm

Here we describe our message passing algorithm for a fixed tree structure $T$. We employ the $\alpha$-divergence framework from Minka (2005). Our variational approximation is fully factorized with a Gaussian $q$ for every variable except $c$ (the divergence function parameter) which is Gamma distributed. For each segment $[ab] \in S(T)$ we introduce two variables which are deterministic functions of existing variables: the
branch length $\Delta_{[ab]} = t_b - t_a$ and the variance $\nu_{[ab]} = \sigma^2 \Delta_{[ab]}$. We now write the unnormalized posterior as a product of factors:

$$
\prod_{n \in \text{leaves}} l(y_n|x_n) \prod_{[ab] \in S(T)} N(x_b; x_a, \nu_{[ab]}) \\
\times \delta(\nu_{[ab]} - \sigma^2 \Delta_{[ab]}) \delta(\Delta_{[ab]} - (t_b - t_a)) \\
\times \mathcal{I}(0 < \Delta_{[ab]} < 1) P(t_b|T)
$$

(3)

where $\delta(.)$ is the Dirac delta spike at 0, and $\mathcal{I}(.)$ is the indicator function. These functions are used to break down more complex factors into simpler ones for computational and mathematical convenience. Equation 3 defines a factor graph over the variables, shown in Figure 2.

**Choosing $\alpha$-divergences.** We choose an $\alpha$ for each factor in the factor graph and then minimize the $\alpha$-divergence $D_{\alpha}(q^2(W) f(W)||q^2(W) f(W))$ with respect to $f(W)$ where $W = \{x, t, \Delta, v\}$ is the set of latent variables for all nodes. Here

$$
D_{\alpha}(p||q) = \frac{1}{\alpha(1 - \alpha)} \int \left( 1 - p(x)^\alpha q(x)^{(1-\alpha)} \right) dx
$$

is the $\alpha$-divergence between two (normalized) distributions $p$ and $q$; and $q^2(W) = q(W)/f(W)$ is the cavity distribution: the current variational posterior without the contribution of factor $f$. Minka (2005) describes how this optimization can be implemented as a message passing algorithm on the factor graph.

We choose which $\alpha$-divergence to minimize for each factor considering performance and computational tractability. The normal, minus, divergence time prior and constraint factors use $\alpha = 1$. The multiplication factor and prior on divergence function parameter $c$ use $\alpha = 0$ (Figure 2). Since we only use $\alpha = 0$ and 1 our algorithm can also be viewed as a hybrid Expectation Propagation (Minka, 2001) and Variational Message Passing (Winn & Bishop, 2006)/mean field (Beal, 2003) algorithm. We use the Infer.NET (Minka et al., 2010) low level library of message updates to calculate the outgoing message from each factor.

Approximating the model evidence is required to drive the search over tree structures (see Section 3.4). Our evidence calculations follow Minka (2005), to which we defer for details. We use the evidence calculated at each iteration to assess convergence.

### 3.2. Message passing in EM algorithm

For high dimensional problems we have found that our message passing algorithm over the divergence times can have convergence problems. This can be addressed using damping, or by maximizing over the divergence times rather than trying to marginalize them. In high dimensional problems the divergence times tend to have more peaked posteriors because each dimension provides independent information on when the divergence times should be. Because of this, and because of the increasing evidence contribution from the increasing number of Gaussian factors in the model at higher dimension $D$, modeling the uncertainty in the divergence times becomes less important. This suggests optimizing the divergence times in an EM type algorithm.

In the E-step, we use message passing to integrate over the locations and hyperparameters. In the M-step we maximize the lower bound on the marginal likelihood with respect to the divergence times. For each node $i$ with divergence time $t_i$ we have the constraints $t_p < t_i < \min(t_l, t_r)$ where $t_l, t_r, t_p$ are the divergence times on the left child, right child and parent of $i$ respectively.

One simple approach is to optimize each divergence time in turn (e.g. using golden section search), performing a co-ordinate ascent. However, we found jointly optimizing the divergence times using LBFGS (Liu & Nocedal, 1989) to be more computationally efficient. Since the divergence times must lie within $[0, 1]$ we use the reparameterization $s_i = \log \left[ t_i/(1-t_i) \right]$ to extend the domain to the whole space, which we find improves empirical performance.

From Equations 2 and 1 the lower bound on the log evidence with respect to an individual divergence time $t_i$ is

$$
\left( c J_{(i),r(i)} - 1 \right) \log (1-t_i) - a \log (t_i - t_p) - \left( \frac{1}{\sigma^2} \right) b_{[pi]}/(t_i - t_p)
$$

where $x_{di}$ is the location of node $i$ in dimension $d$, and $p$ is the parent of node $i$. The full lower bound is the sum of such terms over all nodes. The expectation required for $b_{[pi]}$ is readily calculated from the marginals of the locations after message passing. Differentiating to obtain the gradient with respect to $t_i$ is straightforward so we omit the details. Although this is a constrained optimization problem (branch lengths cannot be negative) it is not necessary to use the log barrier method because the $1/(t_i - t_p)$ terms in the objective implicitly enforce the constraints.

### 3.3. Hyperparameter learning

The DDT has two hyperparameters: the variance of the underlying Brownian motion $\sigma^2$ and the divergence function parameter $c$, which controls the smoothness of the data. For the full message passing framework,
the overall variance $\sigma^2$ is given a Gaussian prior and variational posterior and learnt using the multiplication factor with $\alpha = 0$, corresponding to the mean field divergence measure. For the EM algorithm we use a Gamma prior and variational posterior for $1/\sigma^2$. The message from each segment $[ab]$ to $1/\sigma^2$ is then

$$m_{[ab] \rightarrow 1/\sigma^2} = G\left(\frac{D}{2} + 1, \frac{b_{[p]} - b_{[q]}}{2(t_b - t_a)}\right)$$

where $G(\alpha, \beta)$ is a Gamma distribution with shape $\alpha$ and rate $\beta$, and $b_{[p]}$ is the same as for Equation 4. The smoothness $c$ is given a Gamma prior, and sent the following VMP message from every internal node $i$:

$$\langle \log p(t_i, c) \rangle = \log c + \langle cJ_{(i), r(i)} - 1 \rangle \langle \log (1 - t_i) \rangle$$

$$\Rightarrow m_{i \rightarrow c} = G\left(c; 2, -J_{(i), r(i)} \langle \log (1 - t_i) \rangle\right)$$

The term $\langle \log (1 - t_i) \rangle$ is deterministic for the EM algorithm and is easily approximated under the full message passing algorithm by mapping the Gaussian $q(t_i)$ to a Beta($t_i; \alpha, \beta$) distribution with the same mean and variance, and noting that $\langle \log (1 - t_i) \rangle = \phi(\beta) - \phi(\alpha + \beta)$ where $\phi(\cdot)$ is the digamma function.

3.4. Search over tree structures

Our resulting message passing algorithm approximates the marginal likelihood for a fixed tree structure, $p(y|T)p(T)$ (we include the factor for the probability of the tree structure itself). Ideally we would now sum the marginal likelihood over all possible tree structures $T$ over $N$ leaf nodes. Unfortunately, there are $\frac{(2N)!}{(N+1)!N!}$ such tree structures so that enumeration of all tree structures for even a modest number of leaves is not feasible. Instead we maintain a list of $K$-best trees (typically $K = 10$) which we find gives good empirical performance on a density estimation problem.

We search the space of tree structures by detaching and re-attaching subtrees, which may in fact be single leaves nodes. Central to the efficiency of our method is keeping the messages (and divergence times) for both the main tree and detached subtree so that small changes to the structure only require a few iterations of inference to reconverge.

We experimented with several heuristics for choosing which subtree to detach but none significantly outperformed choosing a subtree at random. However, we greatly improve upon attaching at random. We calculate the local contribution to the evidence that would be made by attaching the root of the subtree to the midpoint of each possible branch. We then run inference on the $L$-best attachments ($L = 3$ worked well, see Figure 5).

**Sequential tree building.** To build an initial tree structure we sequentially process the $N$ leaves. We start with a single internal node with the first two leaves as children. We run inference to convergence on this tree. Given a current tree incorporating the first $n - 1$ leaves, we use the local evidence calculation described above to propose $L$ possible branches at which we could attach leaf $n$. We run inference to convergence on the $L$ resulting trees and choose the one with the best evidence for the next iteration.

**Tree search.** Starting from a random tree or a tree built using the sequential tree building algorithm, we can use tree search to improve the list of $K$-best trees. We detach a subtree at random from the current best
tree, and use the local evidence calculation to propose
$L$ branches at which to re-attach the detached subtree.
We run message passing/EM to convergence in the
resulting trees, add these to the list of trees and keep
only the $K$ best trees in terms of model evidence for
the next iteration.

3.5. Likelihood models
Connecting our DDT module to different likelihood
models is straightforward. We demonstrate a Gaussian
observation model for multivariate continuous data
and a probit model for binary vectors. Both factors
use $\alpha = 1$, corresponding to EP (Minka, 2001).

4. Experiments
We tested our algorithms on both synthetic and real
world data to assess computational and statistical per-
formance both of variants of our algorithms and com-
peting methods. Where computation times are given
these were on a system running Windows 7 Profes-
sional with a Intel Core i7 2.67GHz quadcore processor
and 4GB RAM.

Toy 2D fractal dataset. Our first experiment is
on a simple two dimensional toy example with clear
hierarchical (fractal) structure shown in Figure 3, with
$N = 63$ datapoints. Using the message passing in EM
algorithm with sequential tree building followed by 100
iterations of tree search we obtain the tree shown in
Figure 3 in 7 seconds. The algorithm has recovered the
underlying hierarchical structure of data apart from
the occasional mistake close to the leaves where it is
not clear what the optimal solution should be anyway.

Data from the prior ($D = 5, N = 200$). We use
a dataset sampled from the prior with $\kappa^2 = 1, c = 1$
shown in Figure 4, to assess the different approaches
to tree building and search discussing in Section 3.4.
The results are shown in Figure 5. Eight repeats of
each method were performed using different random
seeds. The slowest method starts with a random tree
and tries randomly re-attaching subtrees (“search ran-
dom”). Preferentially proposing re-attaching subtrees
at the best three positions significantly improves per-
formance (“search greedy”). Sequential tree building is
very fast (5-7 seconds), and can be followed by search
where we only move leaves (“build+search leaves”) or
better, subtrees (“build+search subtrees”). The spread
in initial log evidences for the sequential tree build
methods is due to different permutations of the data
used for the sequential processing. This variation sug-
gests tree building using several random permutations
of the data (potentially in parallel) and then choosing
the best resulting tree.

Figure 5. Performance of different tree building/search
methods on the synthetic dataset.

Macaque skull measurements ($N = 200, D = 10$).
We the macaque skull measurement data of Adams
et al. (2008) to assess our algorithm’s performance
as a density model. Following Adams et al. (2008) we split the 10 dimensional data into 200
training points and 28 test points and model the
three technical repeats separately. We compare to
the infinite mixture of Gaussians (iMOG MCMC)
and DDT MCMC methods implemented in Rad-
ford Neal’s Flexible Bayesian Modeling software (see
http://www.cs.toronto.edu/~radford/). As a
baseline we use a kernel density estimate with band-
width selected using the npudens R package. The re-
sults are shown in Figure 6. The EM version of our
algorithm is able to find a good solution in just a few
tens of seconds, but is eventually beaten on predictive
performance by the MCMC solution. The full mes-
 sage passing solution lies between the MCMC and EM
solutions in terms of speed, and only outperforms the
EM solution on the first of the three repeats. The
DDT based algorithms typically outperform the in-
finite mixture of Gaussians, with the exception of the
second dataset.

Gene expression dataset ($N = 2000, D = 171$).
We apply the EM algorithm with sequential tree build-
ing and 200 iterations of tree search to hierarchical
clustering of the 2000 most variable genes from Yu
& Landsittel (2004). We calculate predictive log like-
lihoods on four splits into 1800 training and 200 test
genes. The results are shown in Table 1. The EM algo-
 rithm for the DDT has comparable statistical perfor-
 mance to the MCMC solution whilst being an order of
magnitude faster. Both implementations significantly
outperform iMOG in terms of predictive performance.
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Figure 3. Toy 2D fractal dataset (N=63) showing learnt tree structure.

Figure 4. First two dimensions of the synthetic dataset from the prior with $D = 5, N = 200, \sigma^2 = 1, c = 1$. Lighter background denotes higher probability density.

Figure 6. Per instance test set performance on the macaque skull measurement data Adams et al. (2008). The three plots arise from using the three technical replicates as separate datasets.

<table>
<thead>
<tr>
<th></th>
<th>iMOG</th>
<th>DDT EM</th>
<th>DDT MCMC</th>
</tr>
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<tbody>
<tr>
<td>Score</td>
<td>$-1.00 \pm 0.04$</td>
<td>$-0.91 \pm 0.02$</td>
<td>$-0.88 \pm 0.03$</td>
</tr>
<tr>
<td>Time</td>
<td>37min</td>
<td>48min</td>
<td>18hours</td>
</tr>
</tbody>
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Table 1. Results on a gene expression dataset (Yu & Land-Sittel, 2004). Score is the per test point, per dimension log predictive likelihood. Time is the average computation time on the system described in Section 4.

DDT MCMC was run for 100 iterations, where one iteration involves sampling the position of every subtree, and the score computed averaging over the last 50 samples. Running DDT MCMC for 5 iterations takes 54min (comparable to the time for EM) and gives a score of $-0.98 \pm 0.04$, worse than DDT EM.

Animal species. To demonstrate the use of an alternative observation model we use a probit observation model in each dimension to model 102-dimensional binary feature vectors relating to attributes (e.g. being warm-blooded, having two legs) of 33 animal species (Kemp & Tenenbaum, 2008). The tree structure we find, shown in Figure 7, is intuitive, with subtrees corresponding to land mammals, aquatic mammals, reptiles, birds, and insects (shown by colour coding).

5. Conclusion

Our approximate inference scheme, combining message passing and greedy tree search, is a computationally attractive alternative to MCMC for DDT models. We have demonstrated the strength of our method for modeling observed continuous and binary data at the leaves, and hope that by making code available we will encourage the community to use this elegant prior over hierarchies. In ongoing work we use the DDT to learn hierarchical structure over latent variables in models including Hidden Markov Models, specifically in part of speech tagging (Kupiec, 1992) where a hierarchy over the latent states aids interpretability, and Latent Dirichlet Allocation, where it is intuitive that topics might be hierarchically clustered (Blei et al., 2004).
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Kingman’s coalescent (Teh et al., 2008) is similar to the Dirichlet Diffusion Tree in spirit although the generative process is defined going backwards in time as datapoints coalesce together, rather than forward in time as for the DDT. Efficient inference for Kingman’s coalescent was demonstrated in Teh & Gorur (2009). We leave investigating whether our framework could be adapted to the coalescent as future work.

References


