Robustness Verification of Tree-based Models

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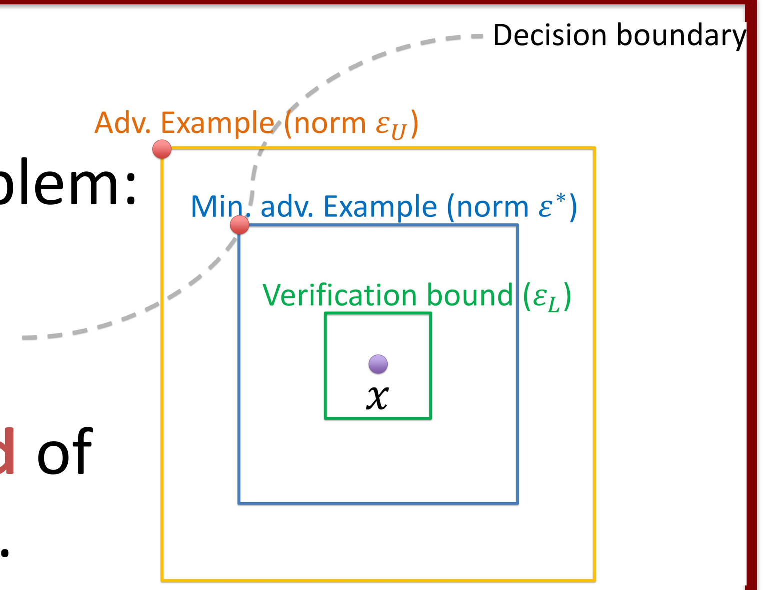
Source code (*XGBoost* compatible!): https://github.com/chenhongge/treeVerification

Introduction



Robustness Verification problem:

$f^*=\min f(x+\delta)$

$\|\delta\|_\infty \leqslant \varepsilon$

We compute a lower bound of f^* and improve it iteratively.

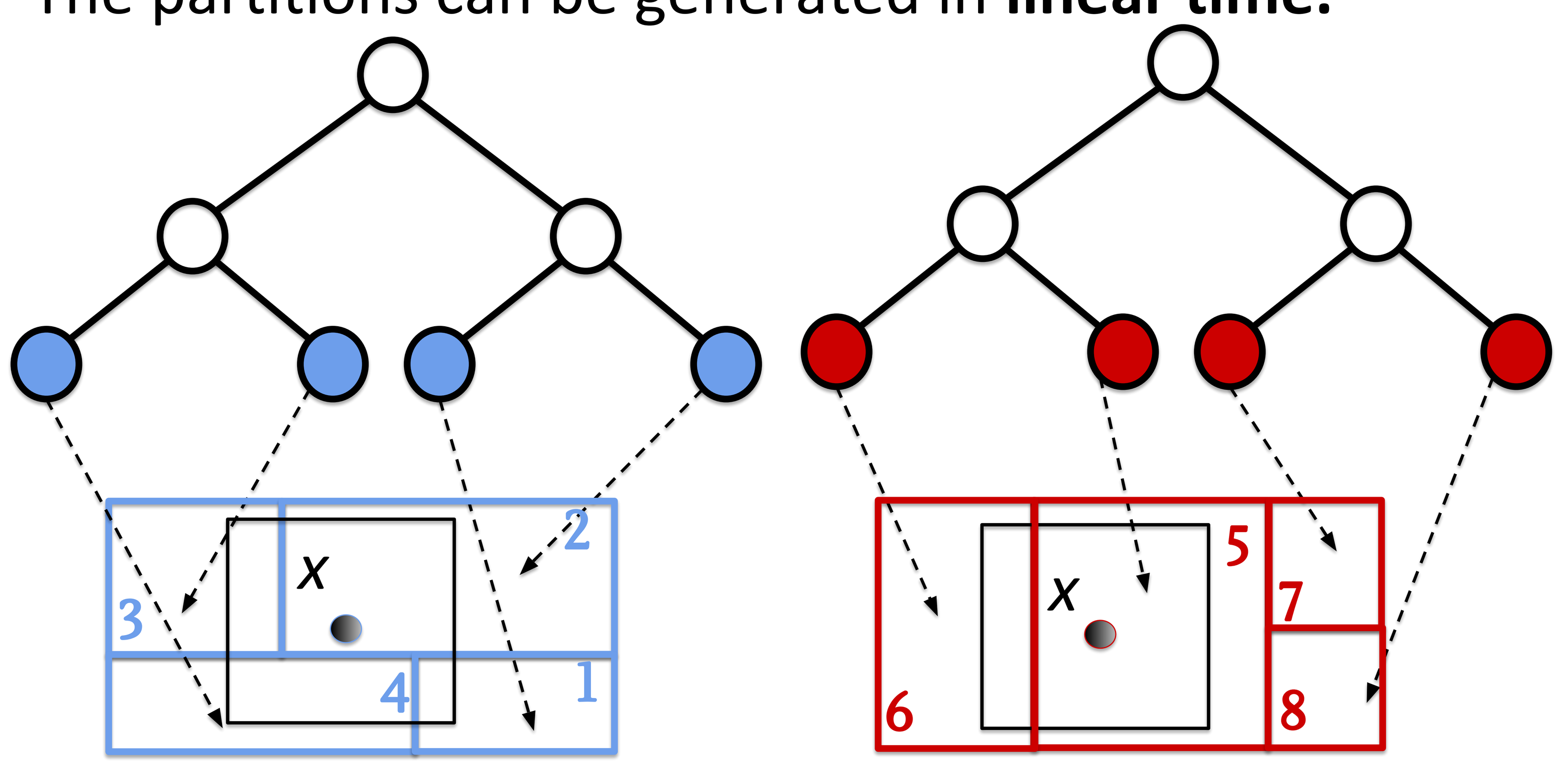
- We verify the robustness for tree based models (include GBDT, random forest, etc)
- Cast as a **max-clique enumeration problem** on a **multi-partite** graph with **bounded boxicity**.
- up to **100X faster** than exact verification, **small gap to f***

Verify your **XGBoost** model today!

https://github.com/chenhongge/treeVerification

Single Tree Verification

Insight: decision tree nodes partition the feature space using boxes, whose boundaries can be tracked. The partitions can be generated in **linear time.**

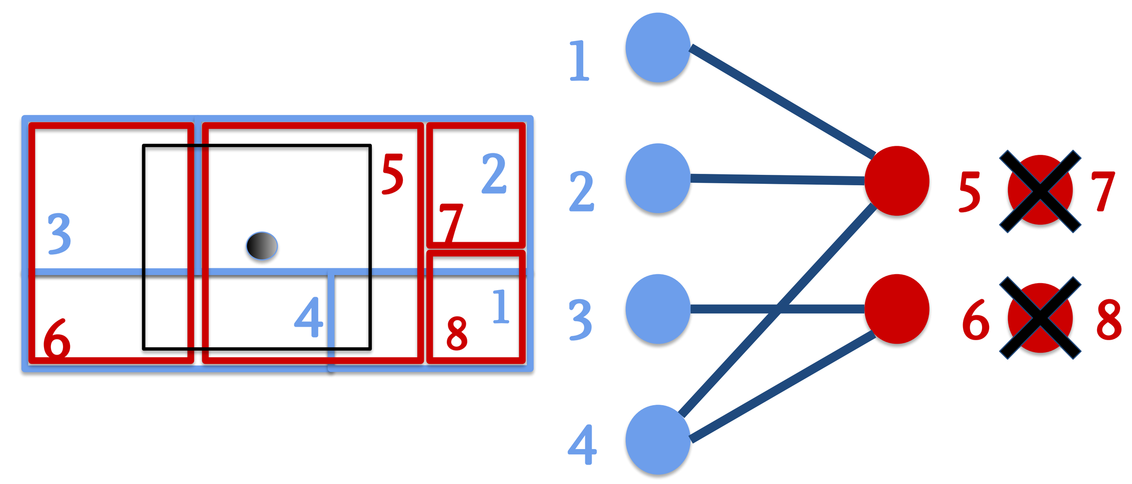


Exact verification of a single tree is easy!

But how to verify a tree ensemble?

- **Naive:** consider the worst case of each tree, and add worst case together (loose bound, but very fast)
- **Ours:** consider multiple trees together using graph theory (much tighter)

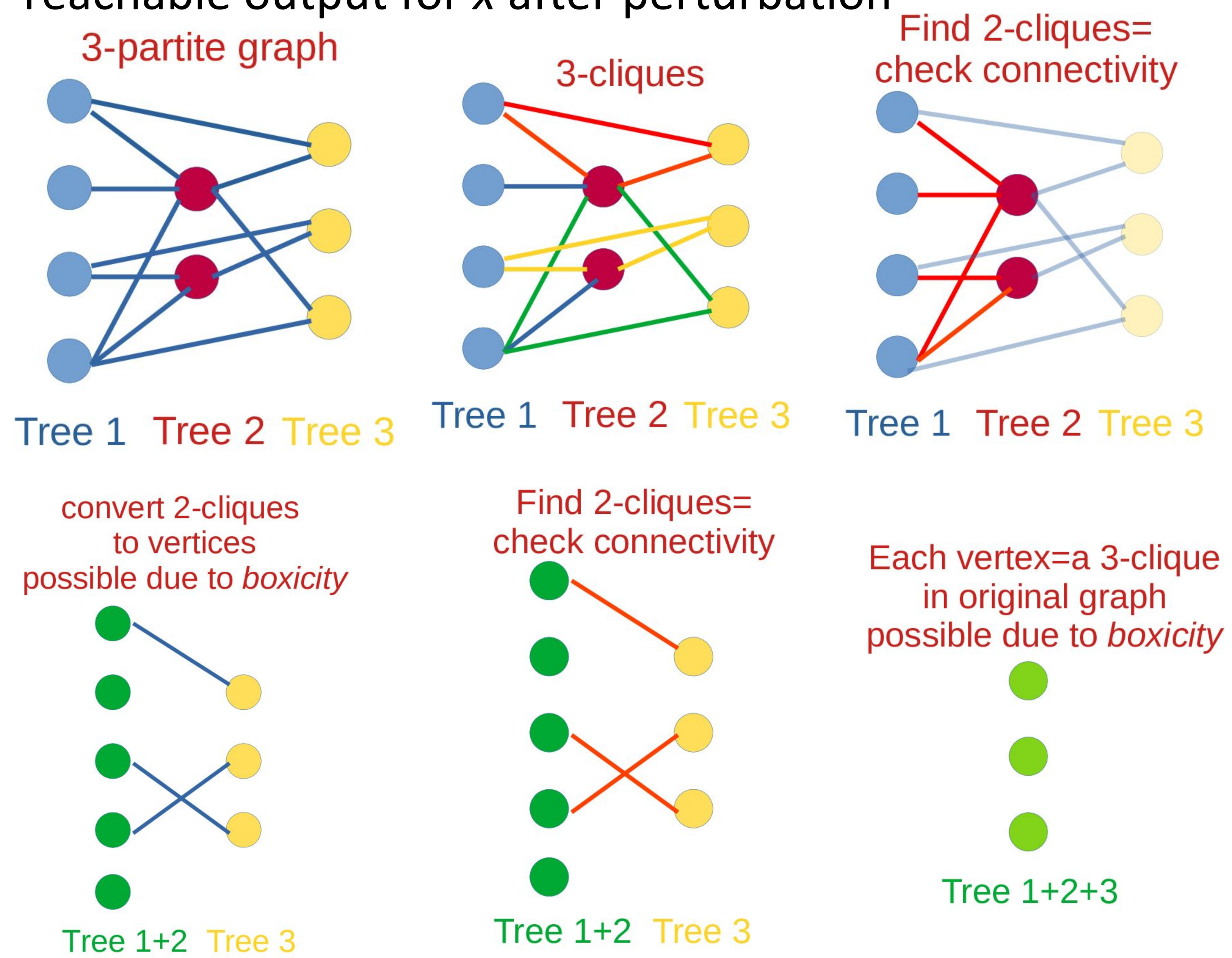
Tree Ensemble Verification



If f(x)>0, we are safe as long as the largest sum of leaf values in all reachable regions is >0.

Theorem: The graph connecting all reachable leaves of **K** trees with **d** features is a **K-paritite** graph with **boxicity d**

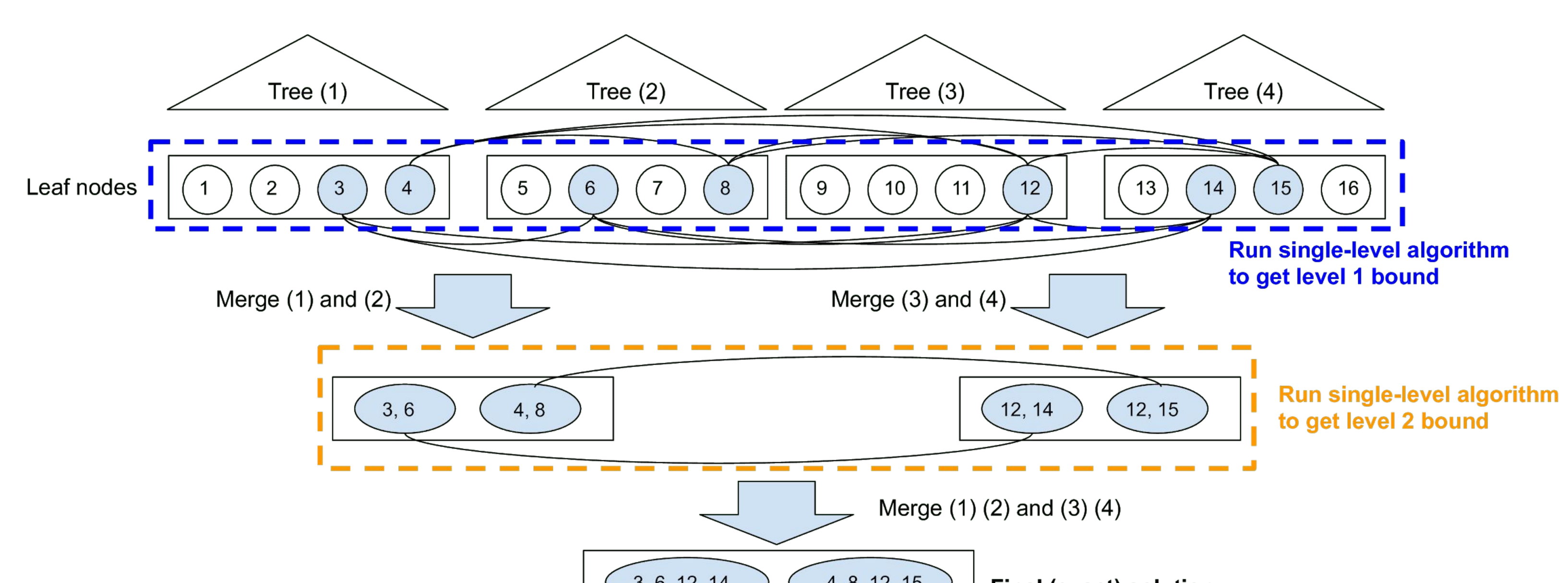
Theorem: Each K-clique of the graph represents a reachable output for *x* after perturbation



Efficient Multi-level Verification

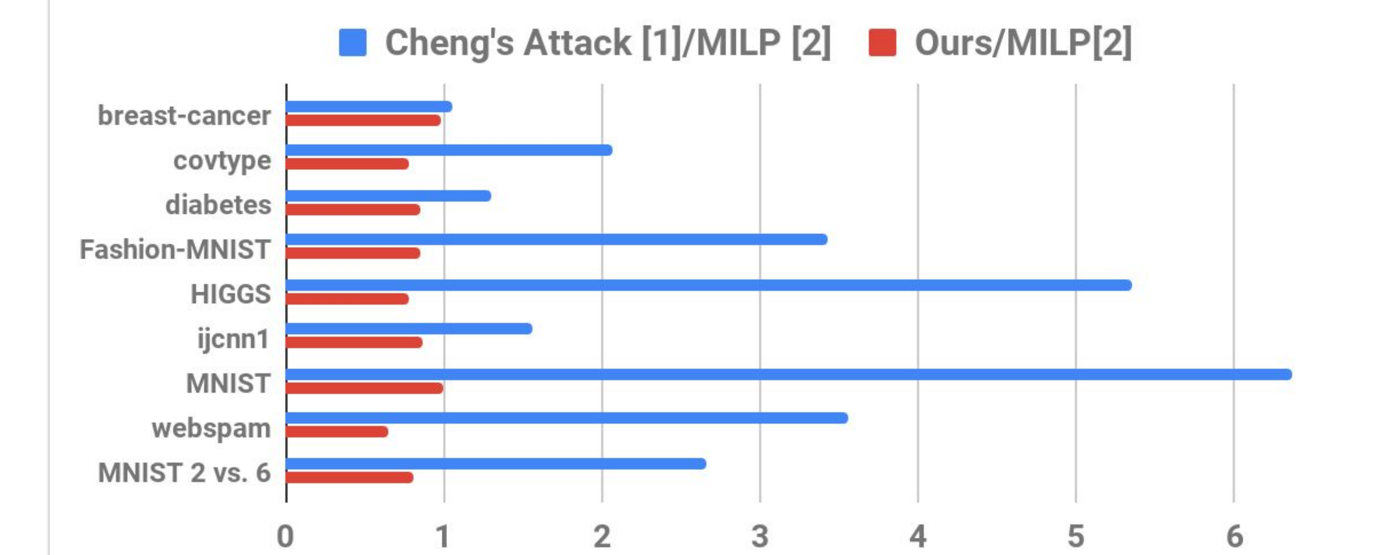
Finding K-cliques on all K trees can be expensive.

We can group K trees to M groups and find (K/M)-cliques inside each group, and use naive bounds between groups

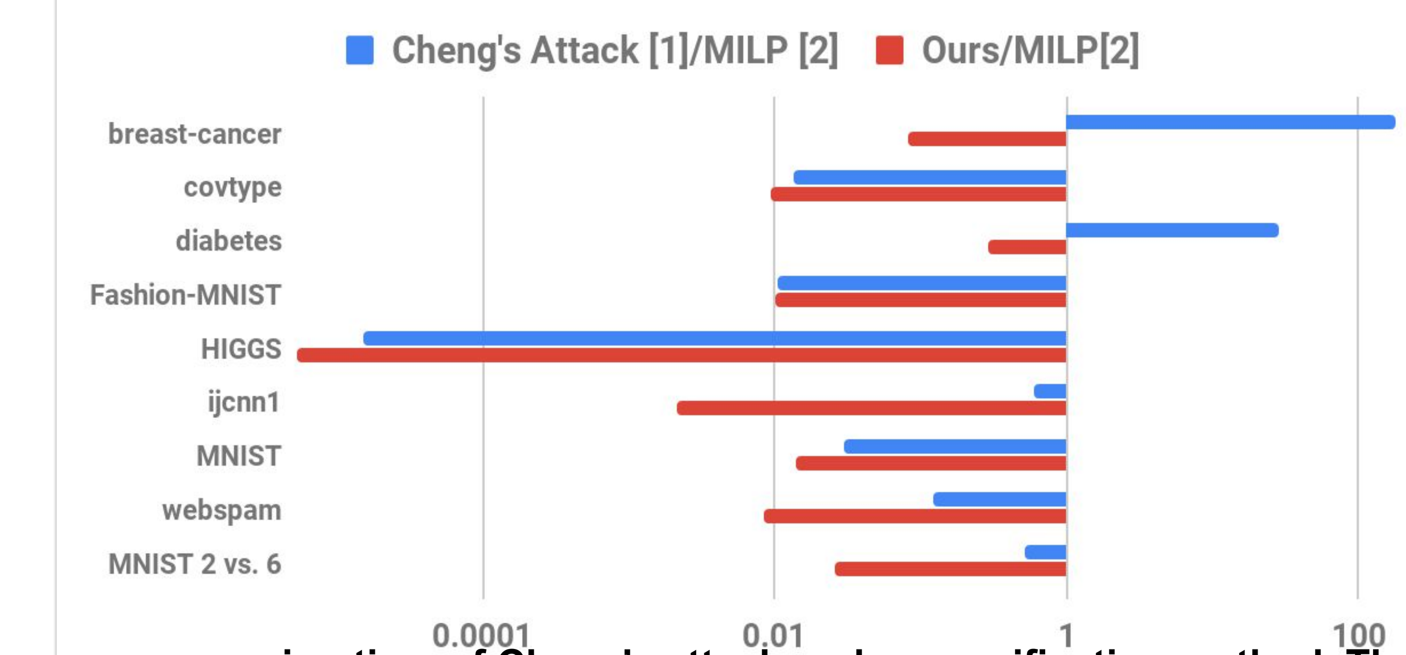


References: [1] Cheng, Minhao, et al. "Query-efficient hard-label black-box attack: An optimization-based approach." ICLR 2019
[2] Kantchelian, Alex, J. D. Tygar, and Anthony Joseph. "Evasion and hardening of tree ensemble classifiers." ICML 2016.
[3] Chen, Hongge, et al. "Robust Decision Trees Against Adversarial Examples." ICML 2019

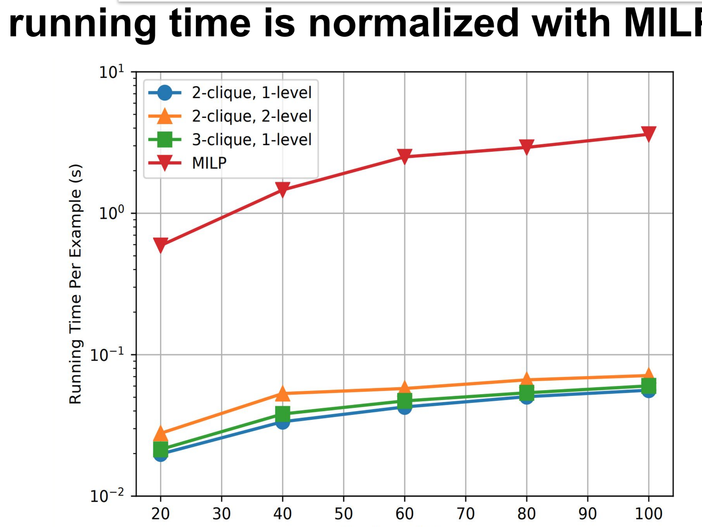
Experiments



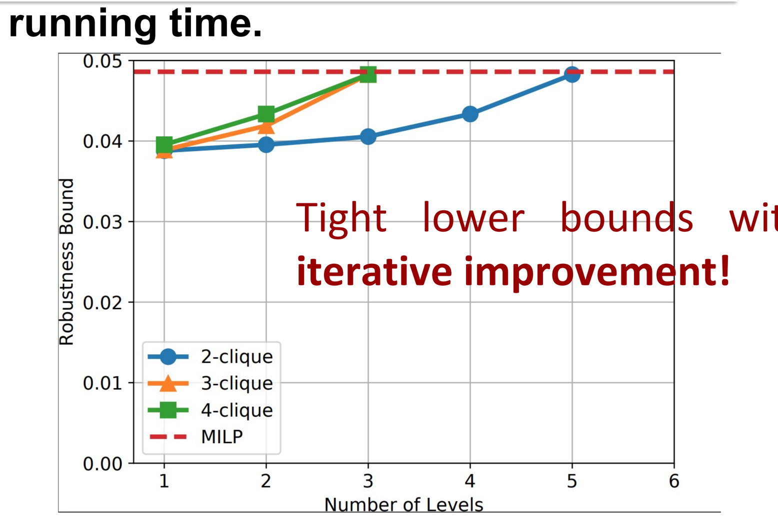
The average ℓ_∞ distance of Cheng's attack [1] and our verification method. The distance is normalized with distance by MILP [2]. Numbers close to 1 indicate a tighter bound.



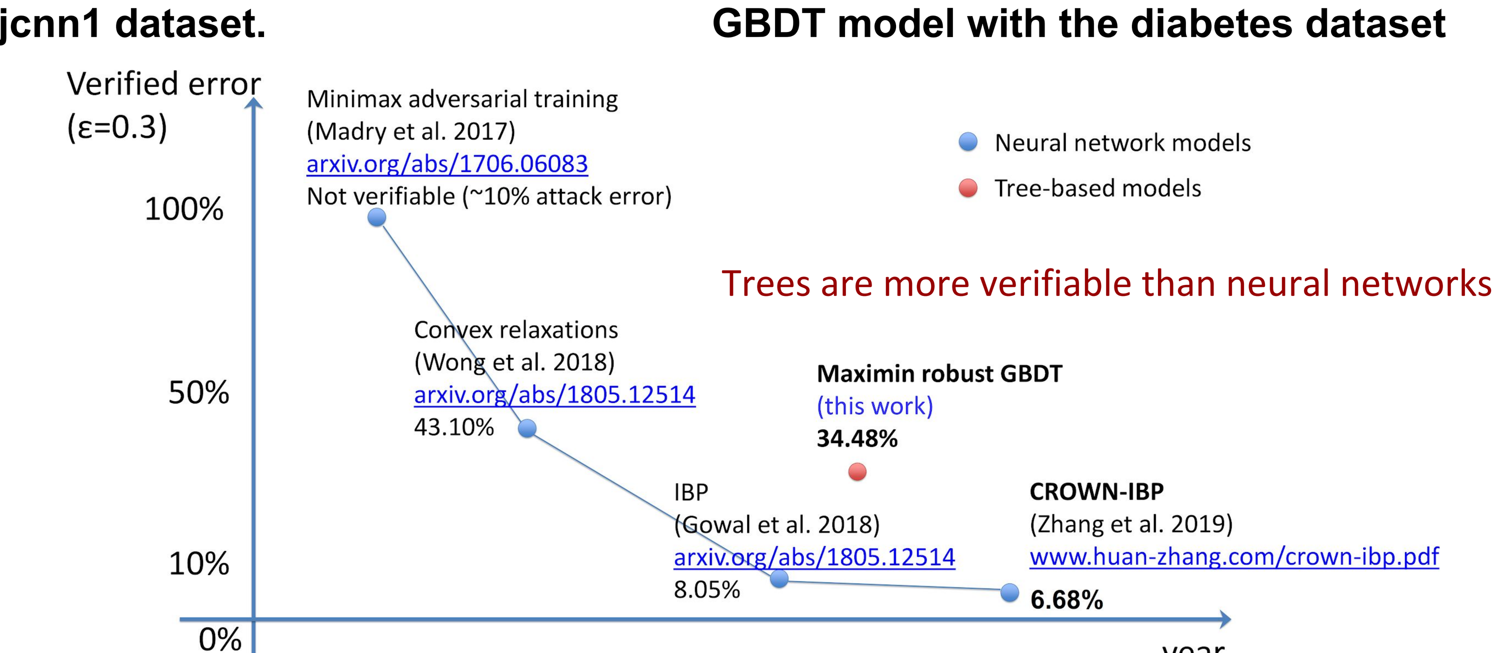
The average running time of Cheng's attack and our verification method. The running time is normalized with MILP's running time.



Running time of MILP and our method on GBDT models with different number of trees on the ijcnn1 dataset.



Robustness bounds obtained with different number of nodes in cliques and different number of levels for searching on a 20-tree GBDT model with the diabetes dataset



Unlike the minimax based adversarial training on deep training, [3] uses a similar maximin robust optimization formulation but can be verified. Compared to DNNs, tree based models are more verifiable (by MILP based exact verification [2] and this work) as tight and fast verification methods are available