ADAPTIVE OPTIMIZERS WITH SPARSE GROUP LASSO

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ABSTRACT

We develop a novel framework that adds the regularizers to a family of adaptive optimizers in deep learning, such as MOMENTUM, ADAGRAD, ADAM, AMSGRAD, ADAHESSIAN, and create a new class of optimizers, which are named GROUP MOMENTUM, GROUP ADAGRAD, GROUP ADAM, GROUP AMSGRAD and GROUP ADAHESSIAN, etc., accordingly. We establish theoretically proven convergence guarantees in the stochastic convex settings, based on primal-dual methods. We evaluate the regularized effect of our new optimizers on three large-scale real-world ad click datasets with state-of-the-art deep learning models. The experimental results reveal that compared with the traditional methods adding regularization terms to the loss functions, not only can the dimensions of features be effectively and efficiently reduced, the performance of the models could also get improved. Furthermore, in comparison to the cases with no regularization terms, our methods can achieve extremely sparsity with highly competitive or significantly better performance.

1 INTRODUCTION

With the development of deep learning, deep neural network (DNN) models have been widely used in various machine learning scenarios such as search, recommendation and advertisement, and achieved significant improvements. In the last decades, different kinds of optimization methods based on the variations of stochastic gradient descent (SGD) have been invented for training DNN models. However, most optimizers cannot directly produce sparsity which has been proven effective and efficient for saving computational resource and improving model performance especially in the scenarios of very high-dimensional data. Meanwhile, the simple rounding approach is very unreliable due to the inherent low accuracy of these optimizers.

In this paper, we develop a new class of optimization methods, that adds the regularizers especially sparse group lasso to prevalent adaptive optimizers, and retains the characteristics of the respective optimizers. Compared with the traditional method which adds the regularizers to the loss, our methods can not only reduce the dimensions of features effectively and efficiently, but also could improve the model performance significantly, and compared with cases of no regularization terms, the new optimizers can produce extremely sparsity with competitive or significantly better performance. In this section, we describe the two types of optimization methods, and explain the motivation of our work.

1.1 ADAPTIVE OPTIMIZATION METHODS

Due to the simplicity and effectiveness, adaptive optimization methods (Robbins & Monro, 1951; Polyak, 1964; Duchi et al., 2011; Zeiler, 2012; Kingma & Ba, 2015; Reddi et al., 2018; Yao et al., 2020) have become the de-facto algorithms used in deep learning. There are multiple variants, but they can be represented using the general update formula (Reddi et al., 2018):

$$x_{t+1} = x_t - \alpha_t m_t / \sqrt{V_t}, \tag{1}$$

where α_t is the step size, m_t is the first moment term which is the weighted average of gradient g_t and V_t is the so called second moment term that adjusts updated velocity of variable x_t in each direction. Here, $\sqrt{V_t} := V_t^{1/2}$, $m_t/\sqrt{V_t} := \sqrt{V_t}^{-1} \cdot m_t$. By setting different m_t, V_t and α_t , we can derive different adaptive optimizers including MOMENTUM (Polyak, 1964), ADAGRAD (Duchi et al., 2011), ADAM (Kingma & Ba, 2015), AMSGRAD (Reddi et al., 2018) and ADAHESSIAN (Yao et al., 2020), etc. See Table 1.

Table 1: Adaptive optimizers with choosing different m_t, V_t and α_t.

Optimizer	$\boldsymbol{m_t}$	$\boldsymbol{V_t}$	$\boldsymbol{\alpha_t}$
SGD	g_t	$\mathbb{I}$	$\frac{\alpha}{\sqrt{t}}$
MOMENTUM	$\gamma m_{t-1} + g_t$	$\mathbb{I}$	α
ADAGRAD	g_t	$\text{diag}(\sum_{i=1}^{t} g_i^2)/t$	$\frac{\alpha}{\sqrt{t}}$
ADAM	$\beta_1 m_{t-1} + (1-\beta_1) g_t$	$\beta_2 V_{t-1} + (1-\beta_2)\text{diag}(g_t^2)$	$\frac{\alpha\sqrt{1-\beta_2^t}}{1-\beta_1^t}$
AMSGRAD	$\beta_1 m_{t-1} + (1-\beta_1) g_t$	$\max(V_{t-1}, \beta_2 V_{t-1} + (1-\beta_2)\text{diag}(g_t^2))$	$\frac{\alpha\sqrt{1-\beta_2^t}}{1-\beta_1^t}$
ADAHESSIAN	$\beta_1 m_{t-1} + (1-\beta_1) g_t$	$\beta_2 V_{t-1} + (1-\beta_2) D_t^2$ *	$\frac{\alpha\sqrt{1-\beta_2^t}}{1-\beta_1^t}$

* $D_t = \text{diag}(H_t)$, where H_t is the Hessian matrix.

1.2 REGULARIZED OPTIMIZATION METHODS

Follow-the-regularized-leader (FTRL) (McMahan & Streeter, 2010; McMahan et al., 2013) has been widely used in click-through rates (CTR) prediction problems, which adds ℓ_1-regularization (lasso) to logistic regression and can effectively balance the performance of the model and the sparsity of features. The update formula (McMahan et al., 2013) is:

$$x_{t+1} = \arg\min_x g_{1:t} \cdot x + \frac{1}{2}\sum_{s=1}^{t} \sigma_s \|x - x_s\|_2^2 + \lambda_1 \|x\|_1, \tag{2}$$

where $g_{1:t} = \sum_{s=1}^{t} g_s$, $\frac{1}{2}\sum_{s=1}^{t} \sigma_s \|x - x_s\|_2^2$ is the strong convex term that stabilizes the algorithm and $\lambda_1 \|x\|_1$ is the regularization term that produces sparsity. However, it doesn't work well in DNN models since one input feature can correspond to multiple weights and lasso only can make single weight zero hence can't effectively delete zeros features.

To solve above problem, Ni et al. (2019) adds the ℓ_{21}-regularization (group lasso) to FTRL, which is named G-FTRL. Yang et al. (2010) conducts the research on a group lasso method for online learning that adds ℓ_{21}-regularization to the algorithm of Dual Averaging (DA) (Nesterov, 2009), which is named DA-GL. Even so, these two methods cannot been applied to other optimizers. Different scenarios are suitable for different optimizers in the deep learning fields. For example, MOMENTUM (Polyak, 1964) is typically used in computer vision; ADAM (Kingma & Ba, 2015) is used for training transformer models for natural language processing; and ADAGRAD (Duchi et al., 2011) is used for recommendation systems. If we want to produce sparsity of the model in some scenario, we have to change optimizer which probably influence the performance of the model.

1.3 MOTIVATION

Eq. (1) can be rewritten into this form:

$$x_{t+1} = \arg\min_x m_t \cdot x + \frac{1}{2\alpha_t} \|\sqrt{V_t}^{\frac{1}{2}}(x - x_t)\|_2^2. \tag{3}$$

Furthermore, we can rewrite Eq. (3) into

$$x_{t+1} = \arg\min_x m_{1:t} \cdot x + \sum_{s=1}^{t} \frac{1}{2\alpha_s} \|Q_s^{\frac{1}{2}}(x - x_s)\|_2^2, \tag{4}$$

where $m_{1:t} = \sum_{s=1}^{t} m_s$, $\sum_{s=1}^{t} Q_s/\alpha_s = \sqrt{V_t}/\alpha_t$. It is easy to prove that Eq. (3) and Eq. (4) are equivalent using the method of induction. The matrices Q_s can be interpreted as generalized learning rates. To our best knowledge, V_t of Eq. (1) of all the adaptive optimization methods are diagonal for the computation simplicity. Therefore, we consider Q_s as diagonal matrices throughout this paper.

We find that Eq. (4) is similar to Eq. (2) except for the regularization term. Therefore, we add the regularization term $\Psi(x)$ to Eq. (4), which is the sparse group lasso penalty also including ℓ_2-

regularization that can diffuse weights of neural networks. The concrete formula is:

$$\Psi_t(x) = \sum_{g=1}^{G} \Big(\lambda_1 \|x^g\|_1 + \lambda_{21} \sqrt{d_{x^g}} \|(\sum_{s=1}^{t} \frac{Q_s^g}{2\alpha_s} + \lambda_2 \mathbb{I})^{\frac{1}{2}} x^g\|_2 \Big) + \lambda_2 \|x\|_2^2, \tag{5}$$

where λ_1, λ_{21}, λ_2 are regularization parameters of ℓ_1, ℓ_{21}, ℓ_2 respectively, G is the total number of groups of weights, x^g is the weights of group g, Q_s^g is the diagonal matrix whose diagonal elements are the part of Q_s corresponding to x_g and d_{x^g} is the size of group g. We add $(\sum_{s=1}^{t} \frac{Q_s^g}{2\alpha_s} + \lambda_2 \mathbb{I})^{\frac{1}{2}}$ to ℓ_{21}-regularization for solving the closed-form solution directly. Obviously, $\|(\sum_{s=1}^{t} \frac{Q_s^g}{2\alpha_s} + \lambda_2 \mathbb{I})^{\frac{1}{2}} x^g\|_2 = 0$ iff $\|x_g\|_2 = 0$. The ultimate update formula is:

$$x_{t+1} = \arg\min_x m_{1:t} \cdot x + \sum_{s=1}^{t} \frac{1}{2\alpha_s} \|Q_s^{\frac{1}{2}}(x - x_s)\|_2^2 + \Psi_t(x). \tag{6}$$

1.4 Outline of Contents

The rest of the paper is organized as follows. In Section 1.5, we introduce the necessary notations and technical background.

In Section 2, we present the closed-form solution of Eq. (4) and the algorithm of general framework of adaptive optimization methods with sparse group lasso. We prove the algorithm is equivalent to adaptive optimization methods when regularization terms vanish. In the end, we give two concrete examples of the algorithm.[1]

In Section 3, we derive the regret bounds of the method and convergence rates.

In Section 4, we validate the performance of new optimziers in the public datasets.

In Section 5, we summarize the conclusion.

Appendices A-B list the details of Group Adam and Group Adagrad respectively. Appendix C-F contain technical proofs of our main results and Appendix G include the details of empirical results.

1.5 Notations and Technical Background

We use lowercase letters to denote scalars and vectors, and uppercase letters to denote matrices. We denote a sequence of vectors by subscripts, that is, $x_1, \ldots, x_t$, and entries of each vector by an additional subscript, e.g., $x_{t,i}$. We use the notation $g_{1:t}$ as a shorthand for $\sum_{s=1}^{t} g_s$. Similarly we write $m_{1:t}$ for a sum of the first moment m_t, and $f_{1:t}$ to denote the function $f_{1:t}(x) = \sum_{s=1}^{t} f_s(x)$. Let $M_t = [m_1 \cdots m_t]$ denote the matrix obtained by concatenating the vector sequence $\{m_t\}_{t \geq 1}$ and $M_{t,i}$ denote the i-th row of this matrix which amounts to the concatenation of the i-th component of each vector. The notation $A \succeq 0$ (resp. $A \succ 0$) for a matrix A means that A is symmetric and positive semidefinite (resp. definite). Similarly, the notations $A \succeq B$ and $A \succ B$ mean that $A - B \succeq 0$ and $A - B \succ 0$ respectively, and both tacitly assume that A and B are symmetric. Given $A \succeq 0$, we write $A^{\frac{1}{2}}$ for the square root of A, the unique $X \succeq 0$ such that $XX = A$ (McMahan & Streeter (2010), Section 1.4).

Let $\mathcal{E}$ be a finite-dimension real vector space, endowed with the Mahalanobis norm $\|\cdot\|_A$ which is denoted by $\|\cdot\|_A = \sqrt{\langle \cdot, A \cdot \rangle}$ as induced by $A \succ 0$. Let $\mathcal{E}^*$ be the vector space of all linear functions on $\mathcal{E}$. The dual space $\mathcal{E}^*$ is endowed with the dual norm $\|\cdot\|_A^* = \sqrt{\langle \cdot, A^{-1} \cdot \rangle}$.

Let $\mathcal{Q}$ be a closed convex set in $\mathcal{E}$. A continuous function $h(x)$ is called *strongly convex* on $\mathcal{Q}$ with norm $\|\cdot\|_H$ if $\mathcal{Q} \subseteq \text{dom } h$ and there exists a constant $\sigma > 0$ such that for all $x, y \in \mathcal{Q}$ and $\alpha \in [0, 1]$ we have

$$h(\alpha x + (1 - \alpha) y) \leq \alpha h(x) + (1 - \alpha) h(y) - \frac{1}{2} \sigma \alpha (1 - \alpha) \|x - y\|_H^2.$$

[1] To fulfill research interest of optimization methods, we will release the code in the future.

The constant σ is called the *convexity parameter* of $h(x)$, or the *modulus* of strong convexity. We also denote by $\|\cdot\|_h = \|\cdot\|_H$. Further, if h is differential, we have

$$h(y) \geq h(x) + \langle \nabla h(x), y - x \rangle + \frac{\sigma}{2}\|x - y\|_h^2.$$

We use online convex optimization as our analysis framework. On each round $t = 1, \ldots, T$, a convex loss function $f_t : \mathcal{Q} \mapsto \mathbb{R}$ is chosen, and we pick a point $x_t \in \mathcal{Q}$ hence get loss $f_t(x_t)$. Our goal is minimizing the *regret* which is defined as the quantity

$$\mathcal{R}_T = \sum_{t=1}^{T} f_t(x_t) - \min_{x \in \mathcal{Q}} \sum_{t=1}^{T} f_t(x). \tag{7}$$

Online convex optimization can be seen as a generalization of stochastic convex optimization. Any regret minimizing algorithm can be converted to a stochastic optimization algorithm with convergence rate $O(\mathcal{R}_T/T)$ using an online-to-batch conversion technique (Gupta et al., 2018).

In this paper, we assume $\mathcal{Q} \equiv \mathcal{E} = \mathbb{R}^n$, hence we have $\mathcal{E}^* = \mathbb{R}^n$. We write $s^T x$ or $s \cdot x$ for the standard inner product between $s, x \in \mathbb{R}^n$. For the standard Euclidean norm, $\|x\| = \|x\|_2 = \sqrt{\langle x, x \rangle}$ and $\|s\|_* = \|s\|_2$. We also use $\|x\|_1 = \sum_{i=1}^n |x^{(i)}|$ and $\|x\|_\infty = \max_i |x^{(i)}|$ to denote ℓ_1-norm and ℓ_∞-norm respectively, where $x^{(i)}$ is the i-th element of x.

2 Algorithm

2.1 Closed-form Solution

We will derive the closed-form solution of Eq. (6) and Algorithm 1 with slight modification in this section. We have the following theorem.

Theorem 1. *Given $z_t = z_{t-1} + m_t - \frac{Q_t}{\alpha_t} x_t$ at each iteration $t = 1, \ldots, T$ and $z_0 = \mathbf{0}$, the optimal solution of Eq.* (6) *is updated accordingly as follows:*

$$x_{t+1} = \Big(\sum_{s=1}^{t} \frac{Q_s}{\alpha_s} + 2\lambda_2 \mathbb{I}\Big)^{-1} \max\Big(1 - \frac{\sqrt{d_{x_t^g}}\lambda_{21}}{\|\tilde{s}_t\|_2}, 0\Big) s_t \tag{8}$$

where the i-th element of s_t is defined as

$$s_{t,i} = \begin{cases} 0 & \text{if } |z_{t,i}| \leq \lambda_1, \\ \operatorname{sign}(z_{t,i})\lambda_1 - z_{t,i} & \text{otherwise,} \end{cases} \tag{9}$$

$\tilde{s}_t$ is defined as

$$\tilde{s}_t = \Big(\sum_{s=1}^{t} \frac{Q_s}{2\alpha_s} + \lambda_2 \mathbb{I}\Big)^{-1} s_t \tag{10}$$

and $\sum_{s=1}^{t} \frac{Q_s}{\alpha_s}$ is the diagonal and positive definite matrix.

The proof of Theorem 1 is given in Appendix C. We slightly modify (8) where we let $\tilde{s}_t = s_t$. Our purpose is to let every entry of the group have the same effect of ℓ_{21}-regularization. Hence, we get Algorithm 1. Furthermore, we have the following theorem which shows the relationship between Algorithm 1 and adaptive optimization methods. The proof is given in Appendix D.

Theorem 2. *If regularization terms of Algorithm 1 vanish, Algorithm 1 is equivalent to Eq.* (1).

2.2 Concrete Examples

Using Algorithm 1, we can easily derive the new optimizers based on Adam (Kingma & Ba, 2015), Adagrad (Duchi et al., 2011) which we call Group Adam, Group Adagrad respectively.

Group Adam

The detail of the algorithm is given in Appendix A. From Theorem 2, we know that when λ_1, λ_2, λ_{21} are all zeros, Algorithm 2 is equivalent to Adam (Kingma & Ba, 2015).

Algorithm 1 Generic framework of adaptive optimization methods with sparse group lasso

Input: parameters $\lambda_1, \lambda_{21}, \lambda_2$
$x_1 \in \mathbb{R}^n$, step size $\{\alpha_t > 0\}_{t=1}^{T}$, sequence of functions $\{\phi_t, \psi_t\}_{t=1}^{T}$, initialize $z_0 = \mathbf{0}, V_0 = \mathbf{0}, \alpha_0 = \mathbf{0}$
for $t = 1$ **to** T **do**
  $g_t = \nabla f_t(x_t)$
  $m_t = \phi_t(g_1, \ldots, g_t)$ and $V_t = \psi_t(g_1, \ldots, g_t)$
  $\frac{Q_t}{\alpha_t} = \frac{\sqrt{V_t}}{\alpha_t} - \frac{\sqrt{V_{t-1}}}{\alpha_{t-1}}$
  $z_t \leftarrow z_{t-1} + m_t - \frac{Q_t}{\alpha_t} x_t$
  for $i \in \{1, \ldots, n\}$ **do**
    $s_{t,i} = \begin{cases} 0 & \text{if } |z_{t,i}| \leq \lambda_1 \\ \text{sign}(z_{t,i})\lambda_1 - z_{t,i} & \text{otherwise.} \end{cases}$
  end for
  $x_{t+1} = (\frac{\sqrt{V_t}}{\alpha_t} + 2\lambda_2 \mathbb{I})^{-1} \max(1 - \frac{\sqrt{d_{x_t^g}}\lambda_{21}}{\|s_t\|_2}, 0) s_t$
end for

GROUP ADAGRAD

The detail of the algorithm is given in Appendix B. Similarly, from Theorem 2, when λ_1, λ_2, λ_{21} are all zeros, Algorithm 3 is equivalent to ADAGRAD (Duchi et al., 2011). Furthermore, we can find that when $\lambda_{21} = 0$, Algorithm 3 is equivalent to FTRL (McMahan et al., 2013). Therefore, GROUP ADAGRAD can also be called GROUP FTRL from the research of Ni et al. (2019).

Similarly, GROUP MOMENTUM, GROUP AMSGRAD, GROUP ADAHESSIAN, etc., can be derived from MOMENTUM (Polyak, 1964), AMSGRAD (Reddi et al., 2018), ADAHESSIAN (Yao et al., 2020), etc., with the same framework and we will not list the details.

3 CONVERGENCE AND REGRET ANALYSIS

Using the framework developed in Nesterov (2009); Xiao (2010); Duchi et al. (2011), we have the following theorem providing the bound of the regret.

Theorem 3. *Let the sequence $\{x_t\}$ be defined by the update* (6) *and*

$$x_1 = \arg\min_{x \in \mathcal{Q}} \frac{1}{2}\|x - c\|_2^2, \tag{11}$$

where c is an arbitrary constant vector. Suppose $f_t(x)$ is convex for any $t \geq 1$ and there exists an optimal solution x^* of $\sum_{t=1}^{T} f_t(x)$, i.e., $x^* = \arg\min_{x \in \mathcal{Q}} \sum_{t=1}^{T} f_t(x)$, which satisfies the condition

$$\langle m_{t-1}, x_t - x^* \rangle \geq 0, \quad t \in [T], \tag{12}$$

where m_t is the weighted average of the gradient $f_t(x_t)$ and $[T] = \{1, \ldots, T\}$ for simplicity. Without loss of generality, we assume

$$m_t = \gamma m_{t-1} + g_t, \tag{13}$$

where $\gamma < 1$ and $m_0 = 0$. Then

$$\mathcal{R}_T \leq \Psi_T(x^*) + \sum_{t=1}^{T} \frac{1}{2\alpha_t} \|Q_t^{\frac{1}{2}}(x^* - x_t)\|_2^2 + \frac{1}{2}\sum_{t=1}^{T} \|m_t\|_{h_{t-1}^*}^2, \tag{14}$$

where $\|\cdot\|_{h_t^*}$ is the dual norm of $\|\cdot\|_{h_t}$. h_t is 1-strongly convex with respect to $\|\cdot\|_{\sqrt{V_t}/\alpha_t}$ for $t \in [T]$ and h_0 is 1-strongly convex with respect to $\|\cdot\|_2$.

The proof of Theorem 3 is given in Appendix E. Since in most of adaptive optimizers, V_t is the weighted average of $\text{diag}(g_t^2)$, without loss of generality, we assume $\alpha_t = \alpha$ and

$$V_t = \eta V_{t-1} + \text{diag}(g_t^2), \quad t \geq 1, \tag{15}$$

where $V_0 = 0$ and $\eta \leq 1$. Hence, we have the following lemma whose proof is given in Appendix F.1.

Lemma 1. *Suppose V_t is the weighted average of the square of the gradient which is defined by* (15)*, $\alpha_t = \alpha$, m_t is defined by* (13) *and V_t satisfies the following arbitrary conditions:*

1. $\eta = 1$,
2. $\eta < 1$, $\eta \geq \gamma$ *and* $\kappa V_t \succeq V_{t-1}$ *for all* $t \geq 1$ *where* $\kappa < 1$.

Then we have

$$\sum_{t=1}^{T} \|m_t\|^2_{(\frac{\sqrt{V_t}}{\alpha_t})^{-1}} < \frac{2\alpha}{1-\nu} \sum_{i=1}^{d} \|M_{T,i}\|_2, \tag{16}$$

where $\nu = \max(\gamma, \kappa)$.

We can always add $\delta^2 \mathbb{I}$ to V_t at each step to ensure $V_t \succ 0$. Therefore, $h_t(x)$ is 1-strongly convex with respect to $\|\cdot\|_{\sqrt{\delta^2 \mathbb{I} + V_t}/\alpha_t}$. Let $\delta \geq \max_{t\in[T]} \|g_t\|_\infty$, for $t > 1$, we have

$$\begin{aligned} \|m_t\|^2_{h^*_{t-1}} &= \left\langle m_t, \alpha_t (\delta^2 \mathbb{I} + V_{t-1})^{-\frac{1}{2}} m_t \right\rangle \leq \left\langle m_t, \alpha_t \left(\text{diag}(g_t^2) + \eta V_{t-1}\right)^{-\frac{1}{2}} m_t \right\rangle \\ &= \left\langle m_t, \alpha_t V_t^{-\frac{1}{2}} m_t \right\rangle = \|m_t\|^2_{(\frac{\sqrt{V_t}}{\alpha_t})^{-1}}. \end{aligned} \tag{17}$$

For $t = 1$, we have

$$\begin{aligned} \|m_1\|^2_{h^*_0} &= \left\langle m_1, \alpha_1 (\delta^2 \mathbb{I} + \mathbb{I})^{-\frac{1}{2}} m_1 \right\rangle \leq \left\langle m_1, \alpha_1 \left(\text{diag}^{-\frac{1}{2}}(g_1^2)\right) m_1 \right\rangle \\ &= \left\langle m_1, \alpha_1 V_1^{-\frac{1}{2}} m_1 \right\rangle = \|m_1\|^2_{(\frac{\sqrt{V_1}}{\alpha_1})^{-1}}. \end{aligned} \tag{18}$$

From (17), (18) and Lemma 1, we have

Lemma 2. *Suppose V_t, m_t, α_t are defined the same as Lemma 1,* $\max_{t\in[T]} \|g_t\|_\infty \leq \delta$, $\|\cdot\|^2_{h^*_t} = \left\langle \cdot, \alpha_t (\delta^2 \mathbb{I} + V_t)^{-\frac{1}{2}} \cdot \right\rangle$ *for $t \geq 1$ and* $\|\cdot\|^2_{h^*_0} = \left\langle \cdot, \alpha_1 \left((\delta^2 + 1)\mathbb{I}\right)^{-\frac{1}{2}} \cdot \right\rangle$. *Then*

$$\sum_{t=1}^{T} \|m_t\|^2_{h^*_{t-1}} < \frac{2\alpha}{1-\nu} \sum_{i=1}^{d} \|M_{T,i}\|_2. \tag{19}$$

Therefore, from Theorem 3 and Lemma 2, we have

Corollary 1. *Suppose V_t, m_t, α_t, h^*_t are defined the same as Lemma 2, there exist constants G, D_1, D_2 such that* $\max_{t\in[T]} \|g_t\|_\infty \leq G \leq \delta$, $\|x^*\|_\infty \leq D_1$ *and* $\max_{t\in[T]} \|x_t - x^*\|_\infty \leq D_2$. *Then*

$$\mathcal{R}_T < dD_1 \left(\lambda_1 + \lambda_{21} (\frac{\sqrt{T}G}{2\alpha} + \lambda_2)^{\frac{1}{2}} + \lambda_2 D_1 \right) + dG \left(\frac{D_2^2}{2\alpha} + \frac{\alpha}{(1-\nu)^2} \right) \sqrt{T}. \tag{20}$$

The proof of Corollary 1 is given in F.2. Furthermore, from Corollary 1, we have

Corollary 2. *Suppose m_t is defined as* (13)*, $\alpha_t = \alpha$ and satisfies the condition* (19)*. There exist constants G, D_1, D_2 such that $tG^2\mathbb{I} \succeq V_t$,* $\max_{t\in[T]} \|g_t\|_\infty \leq G$, $\|x^*\|_\infty \leq D_1$ *and* $\max_{t\in[T]} \|x_t - x^*\|_\infty \leq D_2$. *Then*

$$\mathcal{R}_T < dD_1 \left(\lambda_1 + \lambda_{21} (\frac{\sqrt{T}G}{2\alpha} + \lambda_2)^{\frac{1}{2}} + \lambda_2 D_1 \right) + dG \left(\frac{D_2^2}{2\alpha} + \frac{\alpha}{(1-\nu)^2} \right) \sqrt{T}. \tag{21}$$

Therefore, we know that the regret of the update (6) is $O(\sqrt{T})$ and can achieve the optimal convergence rate $O(1/\sqrt{T})$ under the conditions of Corollary 1 or Corollary 2.

4 EXPERIMENTS

4.1 EXPERIMENT SETUP

We test the algorithms on three different large-scale real-world datasets with different neural network structures. These datasets are various display ads logs for the purpose of predicting ads CTR. The details are as follows.

a) The Avazu CTR dataset (Avazu, 2015) contains approximately 40M samples and 22 categorical features over 10 days. In order to handle categorical data, we use the one-hot-encoding based embedding technique (see, e.g., Wang et al. (2017), Section 2.1 or Naumov et al. (2019), Section 2.1.1) and get 9.4M features in total. For this dataset, the samples from the first 9 days (containing 8.7M one-hot features) are used for training, while the rest is for testing. Our DNN model follows the basic structure of most deep CTR models. Specifically, the model comprises one embedding layer, which maps each one-hot feature into 16-dimensional embeddings, and four fully connected layers (with output dimension of 64, 32, 16 and 1, respectively) in sequence.

b) The iPinYou dataset[2] (iPinYou, 2013) is another real-world dataset for ad click logs over 21 days. The dataset contains 16 categorical features[3]. After one-hot encoding, we get a dataset containing 19.5M instances with 1033.1K input dimensions. We keep the original train/test splitting scheme, where the training set contains 15.4M samples with 937.7K one-hot features. We use Outer Product-based Neural Network (OPNN) (Qu et al., 2016), and follow the standard settings of Qu et al. (2016), i.e., one embedding layer with the embedding dimension of 10, one product layer and three hidden layers of size 512, 256, 128 respectively where we set dropout rate at 0.5.

c) The third dataset is the Criteo Display Ads dataset (Criteo, 2014) which contains approximately 46M samples over 7 days. There are 13 integer features and 26 categorical features. After one-hot encoding of categorical features, we have total 33.8M features. We split the dataset into 7 partitions in chronological order and select the earliest 6 parts for training which contains 29.6M features and the rest for testing though the dataset has no timestamp. We use Deep & Cross Network (DCN) (Wang et al., 2017) and choose the following settings[4]: one embedding layer with embedding dimension 8, two deep layers of size 64 each, and two cross layers.

For the convenience of discussion, we use MLP, OPNN and DCN to represent the aforementioned three datasets coupled with their corresponding models. It is obvious that the embedding layer has most of parameters of the neural networks when the features have very high dimension, therefore we just add the regularization terms to the embedding layer.

We treat the training set as the streaming data, hence we train 1 epoch with a batch size of 512 and do the validation. The experiments are conducted with 4-9 workers and 2-3 parameter servers, which depends on the different sizes of the datasets. We use the area under the receiver-operator curve (AUC) as the evaluation criterion since it is widely used in evaluating classification problems. Besides, some work validates AUC as a good measurement in CTR estimation (Graepel et al., 2010). We explore 5 learning rates from 1e-5 to 1e-1 with increments of 10x and choose the one with the best AUC for each optimizer in the case of no regularization terms. All the experiments are run 5 times repeatedly and tested statistical significance using t-test. Without loss of generality, we choose two new optimizers to validate the performance, which are GROUP ADAM and GROUP ADAGRAD.

4.2 ADAM VS. GROUP ADAM

First, we compare with the performance of adding the regularization term to the loss (traditional method) and the optimizer in producing sparsity. Table 2 of Appendix G reports the average results of adding different values of ℓ_{21} to the loss (ADAM) and the optimizer (GROUP ADAM). Note that GROUP ADAM is consistently significantly better than ADAM in producing sparsity, and comparable or significantly better on then AUC metric in three datasets. Furthermore, as shown in the left

[2]We only use the data from season 2 and 3 because of the same data schema.

[3]See `https://github.com/Atomu2014/Ads-RecSys-Datasets/` for details.

[4]Limited by training resources available, we don't use the optimal hyperparameter settings of Wang et al. (2017).

column of Figure 1 of Appendix G, without postprocessing procedure, the method that adds the regularization term to the loss has no ability to reduce the features which can be deleted as long as all connections to the next layer are zeros, whereas the method that adds the regularization term to the optimizer can produce sparsity increasingly with the growth of ℓ_{21}. And as shown in the right column of Figure 1 of Appendix G, the AUC of ADAM continuously decreases with the increasing of ℓ_{21}, whereas GROUP ADAM keeps almost stable even in extremely sparse cases.

Next, we compare with the performance of ADAM (i.e., GROUP ADAM with no regularization terms) and GROUP ADAM with appropriate regularization terms which we choose in Table 3 of Appendix G on the AUC metric. The results are shown in Table 4 of Appendix G. Note that compared with ADAM, GROUP ADAM with appropriate regularization terms can achieve highly competitive or significantly better performance with producing extremely sparsity.

4.3 ADAGRAD VS. GROUP ADAGRAD

We compare with the performance of ADAGRAD (i.e., GROUP ADAGRAD with no regularization terms) and GROUP ADAGRAD with appropriate regularization terms which we choose in Table 5 of Appendix G on the AUC metric. The results are shown in Table 6 of Appendix G. Again note that in comparison to ADAGRAD, GROUP ADAGRAD can not only achieve highly competitive or significantly better performance of AUC, but also effectively and efficiently reduce the dimensions of the features.

4.4 DISCUSSION

In this section we will discuss the hyperparameters of emdedding dimension, ℓ_1-regularization and ℓ_{21}-regularization to show how these hyperparameters affect the effects of regularization.

Embedding Dimension Table 7 of Appendix G reports the average results of different embedding dimensions of MLP, whose optimizer is GROUP ADAM and regularization terms are same to MLP of Table 5 of Appendix G. Note that the sparsity increases with the growth of the embedding dimension. The reason is that the square root of the embedding dimension is the multiplier of ℓ_{21}-regularization.

$\boldsymbol{\ell_1}$ vs. $\boldsymbol{\ell_{21}}$ Without loss of generality, we choose ℓ_1, ℓ_{21} of 5e-3, 0 respectively, and exchange each other. The results on MLP are shown in Table 8 of Appendix G. It is obvious that ℓ_{21}-regularization is much more effective than ℓ_1-regularization in producing sparsity.

5 CONCLUSION

In this paper, we propose a novel framework that adds the regularization terms to a family of adaptive optimizers for producing sparsity of DNN models. We apply this framework to create a new class of optimizers. We provide closed-form solutions and algorithms with slight modification. We built the relation between new and original optimizers, i.e., our new optimizers become equivalent with the corresponding original ones, once the regularization terms vanish. We theoretically prove the convergence rate of the regret and also conduct empirical evaluation on the proposed optimizers in comparison to the original optimizers that add regularization terms to the loss function as well as to the cases without regularization terms. The results clearly demonstrate the advantages of our proposed optimizers in both producing sparsity and getting highly competitive or significantly better performance.

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APPENDIX

A GROUP ADAM

Algorithm 2 Group Adam

Input: parameters $\lambda_1, \lambda_{21}, \lambda_2, \beta_1, \beta_2, \epsilon$
$x_1 \in \mathbb{R}^n$, step size α, initialize $z_0 = \mathbf{0}, \hat{m}_0 = \mathbf{0}, \hat{V}_0 = \mathbf{0}, V_0 = \mathbf{0}$
for $t = 1$ **to** T **do**
  $g_t = \nabla f_t(x_t)$
  $\hat{m}_t \leftarrow \beta_1 \hat{m}_{t-1} + (1-\beta_1) g_t$
  $m_t = \hat{m}_t / (1-\beta_1^t)$
  $\hat{V}_t \leftarrow \beta_2 \hat{V}_{t-1} + (1-\beta_2)\mathrm{diag}(g_t^2)$
  $V_t = \hat{V}_t / (1-\beta_2^t)$
  $Q_t = \begin{cases} \sqrt{V_t} - \sqrt{V_{t-1}} + \epsilon \mathbb{I} & t = 1 \\ \sqrt{V_t} - \sqrt{V_{t-1}} & t > 1 \end{cases}$
  $z_t \leftarrow z_{t-1} + m_t - \frac{1}{\alpha} Q_t x_t$
  for $i \in \{1, \ldots, n\}$ **do**
    $s_{t,i} = \begin{cases} 0 & \text{if } |z_{t,i}| \leq \lambda_1 \\ \mathrm{sign}(z_{t,i})\lambda_1 - z_{t,i} & \text{otherwise.} \end{cases}$
  end for
  $x_{t+1} = (\frac{\sqrt{V_t} + \epsilon \mathbb{I}}{\alpha} + 2\lambda_2 \mathbb{I})^{-1} \max(1 - \frac{\sqrt{d_{x_t^g}}\lambda_{21}}{\|s_t\|_2}, 0) s_t$
end for

B GROUP ADAGRAD

Algorithm 3 Group Adagrad

Input: parameters $\lambda_1, \lambda_{21}, \lambda_2, \epsilon$
$x_1 \in \mathbb{R}^n$, step size α, initialize $z_0 = \mathbf{0}, V_0 = \mathbf{0}$
for $t = 1$ **to** T **do**
  $g_t = \nabla f_t(x_t)$
  $m_t = g_t$
  $V_t = \begin{cases} V_{t-1} + \mathrm{diag}(g_t^2) + \epsilon \mathbb{I} & t = 1 \\ V_{t-1} + \mathrm{diag}(g_t^2) & t > 1 \end{cases}$
  $Q_t = \sqrt{V_t} - \sqrt{V_{t-1}}$
  $z_t \leftarrow z_{t-1} + m_t - \frac{1}{\alpha} Q_t x_t$
  for $i \in \{1, \ldots, n\}$ **do**
    $s_{t,i} = \begin{cases} 0 & \text{if } |z_{t,i}| \leq \lambda_1 \\ \mathrm{sign}(z_{t,i})\lambda_1 - z_{t,i} & \text{otherwise.} \end{cases}$
  end for
  $x_{t+1} = (\frac{\sqrt{V_t}}{\alpha} + 2\lambda_2 \mathbb{I})^{-1} \max(1 - \frac{\sqrt{d_{x_t^g}}\lambda_{21}}{\|s_t\|_2}, 0) s_t$
end for

C PROOF OF THEOREM 1

Proof.

$$
\begin{aligned}
x_{t+1} &= \arg\min_x m_{1:t} \cdot x + \sum_{s=1}^{t} \frac{1}{2\alpha_s} (x - x_s)^T Q_s (x - x_s) + \Psi(x) \\
&= \arg\min_x m_{1:t} \cdot x + \sum_{s=1}^{t} \frac{1}{2\alpha_s} (\|Q_s^{\frac{1}{2}} x\|_2^2 - 2x \cdot (Q_s x_s) \ + \|Q_s^{\frac{1}{2}} x_s\|_2^2) + \Psi(x) \qquad (22) \\
&= \arg\min_x \left(m_{1:t} - \sum_{s=1}^{t} \frac{Q_s}{\alpha_s} x_s \right) \cdot x + \sum_{s=1}^{t} \frac{1}{2\alpha_s} \|Q_s^{\frac{1}{2}} x\|_2^2 + \Psi(x).
\end{aligned}
$$

Define $z_{t-1} = m_{1:t-1} - \sum_{s=1}^{t-1} \frac{Q_s}{\alpha_s} x_s$ $(t \geq 2)$ and we can calculate z_t as

$$z_t = z_{t-1} + m_t - \frac{Q_t}{\alpha_t} x_t, \quad t \geq 1. \tag{23}$$

By substituting (23), (22) is simplified to be

$$x_{t+1} = \arg\min_x z_t \cdot x + \sum_{s=1}^{t} \frac{Q_s}{2\alpha_s} \|x\|_2^2 + \Psi(x). \tag{24}$$

By substituting $\Psi(x)$ (Eq. (5)) into (24), we get

$$\begin{aligned} x_{t+1} = \arg\min_x z_t \cdot x + \sum_{g=1}^{G} \Big(\lambda_1 \|x^g\|_1 + \lambda_{21} \sqrt{d_{x^g}} \|(\sum_{s=1}^{t} \frac{Q_s^g}{2\alpha_s} + \lambda_2 \mathbb{I})^{\frac{1}{2}} x^g\|_2 \Big) + \\ \|(\sum_{s=1}^{t} \frac{Q_s}{2\alpha_s} + \lambda_2 \mathbb{I})^{\frac{1}{2}} x\|_2^2. \end{aligned} \tag{25}$$

Since the objective of (25) is component-wise and element-wise, we can focus on the solution in one group, say g, and one entry, say i, in the g-th group. Let $\sum_{s=1}^{t} \frac{Q_s^g}{2\alpha_s} = \text{diag}(\sigma_t^g)$ where $\sigma_t^g = (\sigma_{t,1}^g, \ldots, \sigma_{t,d_{x^g}}^g)$. The objective of (25) on $x_{t+1,i}^g$ is

$$\Omega(x_{t+1,i}^g) = z_{t,i}^g x_{t+1,i}^g + \lambda_1 |x_{t+1,i}^g| + \Phi(x_{t+1,i}^g), \tag{26}$$

where $\Phi(x_{t+1,i}^g) = \lambda_{21} \sqrt{d_{x^g}} \|(\sigma_{t,i}^g + \lambda_2)^{\frac{1}{2}} x_{t+1,i}^g\|_2 + \|(\sigma_{t,i}^g + \lambda_2)^{\frac{1}{2}} x_{t+1,i}^g\|_2^2$ is a non-negative function and $\Phi(x_{t+1,i}^g) = 0$ iff $x_{t+1,i}^g = 0$ for all $i \in \{1, \ldots, d_{x^g}\}$.

We discuss the optimal solution of (26) in three cases:

a) If $z_{t,i}^g = 0$, then $x_{t+1,i}^g = 0$.

b) If $z_{t,i}^g > 0$, then $x_{t+1,i}^g \leq 0$. Otherwise, if $x_{t+1,i}^g > 0$, we have $\Omega(-x_{t+1,i}^g) < \Omega(x_{t+1,i}^g)$, which contradicts the minimization value of $\Omega(x)$ on $x_{t+1,i}^g$.

   Next, if $z_{t,i}^g \leq \lambda_1$, then $x_{t+1,i}^g = 0$. Otherwise, if $x_{t+1,i}^g < 0$, we have $\Omega(x_{t+1,i}^g) = (z_{t,i}^g - \lambda_1) x_{t+1,i}^g + \Phi(x_{t+1}^{g,i}) > \Omega(0)$, which also contradicts the minimization value of $\Omega(x)$ on $x_{t+1,i}^g$.

   Third, $z_{t,i}^g > \lambda_1$ $(\forall\, i = 1, \ldots, d_{x^g})$. The objective of (26) for the g-th group, $\Omega(x_{t+1}^g)$, becomes

$$(z_t^g - \lambda_1 \mathbf{1}_{d_{x^g}}) \cdot x_{t+1}^g + \Phi(x_{t+1}^g).$$

c) If $z_{t,i}^g < 0$, the analysis is similar to b). We have $x_{t+1,i}^g \geq 0$. When $-z_{t,i}^g \leq \lambda_1$, $x_{t+1,i}^g = 0$. When $-z_{t,i}^g > \lambda_1$ $(\forall\, i = 1, \ldots, d_{x^g})$, we have

$$\Omega(x_{t+1}^g) = (z_t^g + \lambda_1 \mathbf{1}_{d_{x^g}}) \cdot x_{t+1}^g + \Phi(x_{t+1}^g).$$

From a), b), c) above, we have

$$x_{t+1}^g = \arg\min_x -s_t^g \cdot x + \Phi(x), \tag{27}$$

where the i-th element of s_t^g is defined same as (9).

Define

$$y = (\text{diag}(\sigma_t^g) + \lambda_2 \mathbb{I})^{\frac{1}{2}} x. \tag{28}$$

By substituting (28) into (27), we get

$$y_{t+1}^g = \arg\min_y -\tilde{s}_t^g \cdot y + \lambda_{21} \sqrt{d_{x^g}} \|y\|_2 + \|y\|_2^2, \tag{29}$$

where $\tilde{s}_t^g = (\text{diag}(\sigma_t^g) + \lambda_2 \mathbb{I})^{-1} s_t^g$ which is defined same as (10). This is unconstrained non-smooth optimization problem. Its optimality condition (see Rockafellar (1970), Section 27) states that y_{t+1}^g is an optimal solution if and only if there exists $\xi \in \partial \|y_{t+1}^g\|_2$ such that

$$-\tilde{s}_t^g + \lambda_{21}\sqrt{d_{x^g}}\xi + 2y_{t+1}^g = 0. \tag{30}$$

The subdifferential of $\|y\|_2$ is

$$\partial\|y\|_2 = \begin{cases} \{\zeta \in \mathbb{R}^{d_{x^g}} \,|\, -1 \le \zeta^{(i)} \le 1, i = 1, \ldots, d_{x^g}\} & \text{if } y = 0, \\ \frac{y}{\|y\|_2} & \text{if } y \neq 0. \end{cases}$$

Similarly to the analysis of ℓ_1-regularization, we discuss the solution of (30) in two different cases:

a) If $\|\tilde{s}_t^g\|_2 \le \lambda_{21}\sqrt{d_{x^g}}$, then $y_{t+1}^g = 0$ and $\xi = \frac{\tilde{s}_t^g}{\lambda_{21}\sqrt{d_{x^g}}} \in \partial\|0\|_2$ satisfy (30). We also show that there is no solution other than $y_{t+1}^g = 0$. Without loss of generality, we assume $y_{t+1,i}^g \neq 0$ for all $i \in \{1, \ldots, d_{x^g}\}$, then $\xi = \frac{y_{t+1}^g}{\|y_{t+1}^g\|_2}$, and

$$-\tilde{s}_t^g + \frac{\lambda_{21}\sqrt{d_{x^g}}}{\|y_{t+1}^g\|_2} y_{t+1}^g + 2y_{t+1}^g = 0. \tag{31}$$

From (31), we can derive

$$(\frac{\lambda_{21}\sqrt{d_{x^g}}}{\|y_{t+1}^g\|_2} + 2)\|y_{t+1}^g\|_2 = \|\tilde{s}_t^g\|_2.$$

Furthermore, we have

$$\|y_{t+1}^g\|_2 = \frac{1}{2}(\|\tilde{s}_t^g\|_2 - \lambda_{21}\sqrt{d_{x^g}}), \tag{32}$$

where $\|y_{t+1}^g\|_2 > 0$ and $\|\tilde{s}_t^g\|_2 - \lambda_{21}\sqrt{d_{x^g}} \le 0$ contradict each other.

b) If $\|\tilde{s}_t^g\|_2 > \lambda_{21}\sqrt{d_{x^g}}$, then from (31) and (32), we get

$$y_{t+1}^g = \frac{1}{2}(1 - \frac{\lambda_{21}\sqrt{d_{x^g}}}{\|\tilde{s}_t^g\|_2})\tilde{s}_t^g. \tag{33}$$

We replace y_{t+1}^g of (33) by x_{t+1}^g using (28), then we have

$$\begin{aligned} x_{t+1}^g &= (\text{diag}(\sigma_t^g) + \lambda_2 \mathbb{I})^{-\frac{1}{2}} y_{t+1}^g \\ &= (2\text{diag}(\sigma_t^g) + 2\lambda_2 \mathbb{I})^{-1}(1 - \frac{\lambda_{21}\sqrt{d_{x^g}}}{\|\tilde{s}_t^g\|_2}) s_t^g \\ &= (\sum_{s=1}^{t} \frac{Q_s}{\alpha_s} + 2\lambda_2 \mathbb{I})^{-1}(1 - \frac{\lambda_{21}\sqrt{d_{x^g}}}{\|\tilde{s}_t^g\|_2}) s_t^g. \end{aligned} \tag{34}$$

Combine a) and b) above, we finish the proof. □

D Proof of Theorem 2

Proof. We use the method of induction.

a) When $t = 1$, then Algorithm 1 becomes

$$\begin{aligned} Q_1 &= \alpha_1(\frac{\sqrt{V_1}}{\alpha_1} - \frac{\sqrt{V_0}}{\alpha_0}) = \sqrt{V_1}, \\ z_1 &= z_0 + m_1 - \frac{Q_1}{\alpha_1} x_1 = m_1 - \frac{\sqrt{V_1}}{\alpha_1} x_1, \\ s_1 &= -z_1 = \frac{\sqrt{V_1}}{\alpha_1} x_1 - m_1, \\ x_2 &= (\frac{\sqrt{V_1}}{\alpha_1})^{-1} s_1 = x_1 - \alpha_1 \frac{m_1}{\sqrt{V_1}}, \end{aligned}$$

which equals to Eq. (1).

b) Assume $t = T$, Eq. (35) are true.

$$z_T = m_T - \frac{\sqrt{V_T}}{\alpha_T} x_T, \quad x_{T+1} = x_T - \alpha_T \frac{m_T}{\sqrt{V_T}}. \tag{35}$$

For $t = T + 1$, we have

$$\begin{aligned}
z_{T+1} &= z_T + m_{T+1} - \frac{Q_{T+1}}{\alpha_{T+1}} x_{T+1} \\
&= m_T - \frac{\sqrt{V_T}}{\alpha_T} x_T + m_{T+1} - \frac{Q_{T+1}}{\alpha_{T+1}} x_{T+1} \\
&= m_T - \frac{\sqrt{V_T}}{\alpha_T} (x_{T+1} + \alpha_T \frac{m_T}{\sqrt{V_T}}) + m_{T+1} - \frac{Q_{T+1}}{\alpha_{T+1}} x_{T+1} \\
&= m_{T+1} - (\frac{\sqrt{V_T}}{\alpha_T} + \frac{Q_{T+1}}{\alpha_{T+1}}) x_{T+1} = m_{T+1} - \frac{\sqrt{V_{T+1}}}{\alpha_{T+1}} x_{T+1}, \\
x_{T+2} &= (\frac{\sqrt{V_{T+1}}}{\alpha_{T+1}})^{-1} s_{T+1} = -(\frac{\sqrt{V_{T+1}}}{\alpha_{T+1}})^{-1} z_{T+1} = x_{T+1} - \alpha_T \frac{m_{T+1}}{\sqrt{V_{T+1}}}.
\end{aligned}$$

Hence, we complete the proof. □

E Proof of Theorem 3

Proof. Let

$$h_t(x) = \begin{cases} \sum_{s=1}^{t} \frac{1}{2\alpha_s} \|Q_s^{\frac{1}{2}}(x - x_s)\|_2^2 & \forall\, t \in [T], \\ \frac{1}{2}\|x - c\|_2^2 & t = 0. \end{cases}$$

It is easy to verify that for all $t \in [T]$, $h_t(x)$ is 1-strongly convex with respect to $\|\cdot\|_{\sqrt{V_t}/\alpha_t}$ which $\frac{\sqrt{V_t}}{\alpha_t} = \sum_{s=1}^{t} \frac{Q_s}{\alpha_s}$, and $h_0(x)$ is 1-strongly convex with respect to $\|\cdot\|_2$.

From (7), we have

$$\begin{aligned}
\mathcal{R}_T &= \sum_{t=1}^{T} (f_t(x_t) - f_t(x^*)) \le \sum_{t=1}^{T} \langle g_t, x_t - x^* \rangle \\
&= \sum_{t=1}^{T} \langle m_t - \gamma m_{t-1}, x_t - x^* \rangle \le \sum_{t=1}^{T} \langle m_t, x_t - x^* \rangle \\
&= \sum_{t=1}^{T} \langle m_t, x_t \rangle + \Psi_T(x^*) + h_T(x^*) + (\sum_{t=1}^{T} \langle -m_t, x^* \rangle - \Psi_T(x^*) - h_T(x^*)) \\
&\le \sum_{t=1}^{T} \langle m_t, x_t \rangle + \Psi_T(x^*) + h_T(x^*) + \sup_{x \in \mathcal{Q}} \{\langle -m_{1:T}, x \rangle - \Psi_T(x) - h_T(x)\},
\end{aligned} \tag{36}$$

where in the first and second inequality above, we use the convexity of $f_t(x)$ and the condition (12) respectively.

We define $h_t^*(u)$ to be the conjugate dual of $\Psi_t(x) + h_t(x)$:

$$h_t^*(u) = \sup_{x \in \mathcal{Q}} \{\langle u, x \rangle - \Psi_t(x) - h_t(x)\}, \quad t \ge 0,$$

where $\Psi_0(x) = 0$. Since $h_t(x)$ is 1-strongly convex with respect to the norm $\|\cdot\|_{h_t}$, the function h_t^* has 1-Lipschitz continuous gradients with respect to $\|\cdot\|_{h_t^*}$ (see, Nesterov (2005), Theorem 1):

$$\|\nabla h_t^*(u_1) - \nabla h_t^*(u_2)\|_{h_t} \le \|u_1 - u_2\|_{h_t^*}, \tag{37}$$

and

$$\nabla h_t^*(u) = \arg\min_{x \in \mathcal{Q}} \{-\langle u, x \rangle + \Psi_t(x) + h_t(x)\}. \tag{38}$$

As a trivial corollary of (37), we have the following inequality:

$$h_t^*(u+\delta) \leq h_t^*(u) + \langle \nabla h_t^*(u), \delta \rangle + \frac{1}{2}\|\delta\|_{h_t^*}^2. \tag{39}$$

Since $h_{t+1}(x) \geq h_t(x)$ and $\Psi_{t+1}(x) \geq \Psi_t(x)$, from (38), (39), (6), we have

$$\begin{aligned} h_T^*(-m_{1:T}) &\leq h_{T-1}^*(-m_{1:T}) \\ &\leq h_{T-1}^*(-m_{1:T-1}) - \left\langle \nabla h_{T-1}^*(-m_{1:T-1}), m_T \right\rangle + \frac{1}{2}\|m_T\|_{h_{T-1}^*}^2 \\ &\leq h_{T-2}^*(-m_{1:T-1}) - \langle x_T, m_T \rangle + \frac{1}{2}\|m_T\|_{h_{T-1}^*}^2 \\ &\leq h_0^*(0) - \langle \nabla h_0^*(0), m_1 \rangle - \sum_{t=2}^{T} \langle x_t, m_t \rangle + \frac{1}{2}\sum_{t=2}^{T} \|m_t\|_{h_{t-1}^*}^2 \\ &= -\sum_{t=1}^{T} \langle x_t, m_t \rangle + \frac{1}{2}\sum_{t=1}^{T} \|m_t\|_{h_{t-1}^*}^2. \end{aligned} \tag{40}$$

where the last equality above follows from $h_0^*(0) = 0$ and (11) which deduces $x_1 = \nabla h_0^*(0)$.

By substituting (40), (36) becomes

$$\begin{aligned} \mathcal{R}_T &\leq \sum_{t=1}^{T} \langle m_t, x_t \rangle + \Psi_T(x^*) + h_T(x^*) + h_T^*(-m_{1:T}) \\ &\leq \Psi_T(x^*) + h_T(x^*) + \frac{1}{2}\sum_{t=1}^{T} \|m_t\|_{h_{t-1}^*}^2. \end{aligned} \tag{41}$$

□

F Additional Proofs

F.1 Proof of Lemma 1

Proof. Let $V_t = \mathrm{diag}(\sigma_t)$ where σ_t is the vector of the diagonal elements of V_t. For i-th entry of σ_t, by substituting (13) into (15), we have

$$\begin{aligned} \sigma_{t,i} &= g_{t,i}^2 + \eta\sigma_{t-1,i} = (m_{t,i} - \gamma m_{t-1,i})^2 + \eta g_{t-1,i}^2 + \eta^2 \sigma_{t-2,i} \\ &= \sum_{s=1}^{t} \eta^{t-s}(m_{s,i} - \gamma m_{s-1,i})^2 \geq \sum_{s=1}^{t} \eta^{t-s}(1-\gamma)(m_{s,i}^2 - \gamma m_{s-1,i}^2) \\ &= (1-\gamma)\Big(m_{t,i}^2 + (\eta - \gamma)\sum_{s=1}^{t-1} \eta^{t-s-1} m_{s,i}^2\Big). \end{aligned} \tag{42}$$

Next, we will discuss the value of η in two cases.

a) $\eta = 1$. From (42), we have

$$\sigma_{t,i} \geq (1-\gamma)\Big(m_{t,i}^2 + (1-\gamma)\sum_{s=1}^{t-1} m_{s,i}^2\Big) > (1-\gamma)^2 \sum_{s=1}^{t} m_{s,i}^2 \geq (1-\nu)^2 \sum_{s=1}^{t} m_{s,i}^2. \tag{43}$$

Recalling the definition of $M_{t,i}$ in Section 1.5, from (43), we have

$$\sum_{t=1}^{T} \frac{m_{t,i}^2}{\sqrt{\sigma_{t,i}}} < \frac{1}{1-\nu}\sum_{t=1}^{T} \frac{m_{t,i}^2}{\|M_{t,i}\|_2} \leq \frac{2}{1-\nu}\|M_{T,i}\|_2,$$

where the last inequality above follows from Appendix C of Duchi et al. (2011). Therefore, we get

$$\sum_{t=1}^{T} \|m_t\|^2_{(\frac{\sqrt{V_t}}{\alpha_t})^{-1}} = \alpha \sum_{t=1}^{T}\sum_{i=1}^{d} \frac{m_{t,i}^2}{\sqrt{\sigma_{t,i}}} < \frac{2\alpha}{1-\nu}\sum_{i=1}^{d} \|M_{T,i}\|_2. \tag{44}$$

b) $\eta < 1$. We assume $\eta \geq \gamma$ and $\kappa V_t \succeq V_{t-1}$ where $\kappa < 1$, then we have

$$\sum_{s=1}^{t} \kappa^{t-s} \sigma_{t,i} \geq \sum_{s=1}^{t} \sigma_{s,i} \geq (1-\gamma) \sum_{s=1}^{t} m_{s,i}^2.$$

Hence, we get

$$\sigma_{t,i} \geq \frac{1-\kappa}{1-\kappa^t}(1-\gamma) \sum_{s=1}^{t} m_{s,i}^2 > (1-\kappa)(1-\gamma) \sum_{s=1}^{t} m_{s,i}^2 \geq (1-\nu)^2 \sum_{s=1}^{t} m_{s,i}^2, \tag{45}$$

which deduces the same conclusion (44) of a).

Combine a) and b), we complete the proof. □

F.2 Proof of Corollary 1

Proof. From the definition of m_t (13), V_t (15), we have

$$|m_{t,i}| = |\sum_{s=1}^{t} \gamma^{t-s} g_{s,i}| \leq \frac{1-\gamma^t}{1-\gamma} G < \frac{G}{1-\gamma} \leq \frac{G}{1-\nu},$$

$$|\sigma_{t,i}| = |\sum_{s=1}^{t} \eta^{t-s} g_{s,i}^2| \leq tG^2.$$

Hence, we have

$$\Psi_T(x^*) \leq \lambda_1 d D_1 + \lambda_{21} d D_1 (\frac{\sqrt{T}G}{2\alpha} + \lambda_2)^{\frac{1}{2}} + \lambda_2 d D_1^2, \tag{46}$$

$$h_T(x^*) \leq \frac{d D_2^2 G}{2\alpha} \sqrt{T}, \tag{47}$$

$$\frac{1}{2} \sum_{t=1}^{T} \|m_t\|_{h_{t-1}^*}^2 < \frac{\alpha}{1-\nu} \sum_{i=1}^{d} \frac{\sqrt{T}G}{1-\nu} = \frac{d\alpha G}{(1-\nu)^2} \sqrt{T}. \tag{48}$$

Combining (46), (47), (48), we complete the proof. □

G Empirical Results

Table 2: AUC for different values of ℓ_{21} and sparsity (feature rate) in parentheses. The best results are bolded (achieved by t-test with 95% confidence level).

ℓ_{21}	MLP		OPNN		DCN	
	Adam	Group Adam	Adam	Group Adam	Adam	Group Adam
1e-4	0.7467±0.0012 (1.000±0.000)	0.7461±0.0005 (**0.974**±0.004)	0.7566±0.0025 (1.000±0.000)	0.7595±0.0042 (**0.078**±0.002)	0.8017±0.0001 (1.000±0.000)	**0.8022**±0.0002 (**0.518**±0.007)
5e-4	0.7454±0.0009 (1.000±0.000)	**0.7468**±0.0007 (**0.864**±0.009)	0.7476±0.0024 (1.000±0.000)	**0.7573**±0.0013 (**0.039**±0.002)	0.7987±0.0004 (1.000±0.000)	**0.8019**±0.0004 (**0.062**±0.003)
1e-3	0.7449±0.0004 (1.000±0.000)	**0.7468**±0.0008 (**0.701**±0.021)	0.7308±0.0052 (1.000±0.000)	**0.7595**±0.0033 (**0.032**±0.001)	0.7979±0.0008 (1.000±0.000)	**0.8017**±0.0003 (**0.018**±0.001)
5e-3	0.7403±0.0004 (1.000±0.000)	**0.7464**±0.0013 (**0.132**±0.025)	0.6519±0.0068 (1.000±0.000)	**0.7561**±0.0030 (**0.018**±0.000)	0.7948±0.0002 (1.000±0.000)	**0.8007**±0.0004 (**0.004**±0.000)
1e-2	0.7379±0.0002 (1.000±0.000)	**0.7466**±0.0011 (**0.038**±0.002)	0.6352±0.0111 (1.000±0.000)	**0.7493**±0.0023 (**0.009**±0.000)	0.7924±0.0006 (1.000±0.000)	**0.7999**±0.0003 (**0.002**±0.000)

Table 3: The regularization terms of GROUP ADAM of three datasets.

Dataset	ℓ_1	ℓ_{21}	ℓ_2
MLP	5e-3	1e-2	1e-5
OPNN	8e-5	1e-5	1e-5
DCN	4e-4	5e-4	1e-5

Table 4: AUC for three datasets and sparsity (feature rate) in parentheses. The best results are bolded (achieved by t-test with 95% confidence level).

Dataset	ADAM	GROUP ADAM
MLP	0.7458±0.0005 (1.000±0.000)	**0.7486**±0.0010 (**0.018**±0.003)
OPNN	0.7588±0.0028 (0.827±0.000)	0.7617±0.0048 (**0.130**±0.003)
DCN	0.8021±0.0003 (1.000±0.000)	0.8019±0.0003 (**0.030**±0.003)

Table 5: The regularization terms of GROUP ADAGRAD of three datasets.

Dataset	ℓ_1	ℓ_{21}	ℓ_2
MLP	0	1e-2	1e-5
OPNN	8e-5	8e-5	1e-5
DCN	0	4e-3	1e-5

Table 6: AUC for three datasets and sparsity (feature rate) in parentheses. The best results are bolded (achieved by t-test with 95% confidence level).

Dataset	ADAGRAD	GROUP ADAGRAD
MLP	0.7453±0.0010 (1.000±0.000)	0.7469±0.0016 (**0.063**±0.008)
OPNN	0.7556±0.0022 (0.827±0.000)	**0.7595**±0.0023 (**0.016**±0.001)
DCN	0.7975±0.0003 (1.000±0.000)	0.7978±0.0004 (**0.040**±0.003)

Table 7: AUC of MLP for different embedding dimensions and sparsity (feature rate) in parentheses. The best results are bolded (achieved by t-test with 95% confidence level).

Embedding Dimension	GROUP ADAM
4	0.7462±0.0007 (0.123±0.009)
8	0.7471±0.0009 (0.056±0.005)
16	0.7486*±0.0010 (0.018±0.003)
32	0.7480±0.0004 (**0.006**±0.000)

* It is significantly better than embedding dimensions of 4, 8 but has no difference in 95% confidence level of the embedding dimension of 32.

Table 8: AUC of MLP for different values of ℓ_1, ℓ_{21} and sparsity (feature rate) in parentheses. The best results are bolded (achieved by t-test with 95% confidence level).

ℓ_1	ℓ_{21}	GROUP ADAM
5e-3	0	0.7481±0.0011 (0.470±0.044)
0	5e-3	0.7485±0.0004 (**0.136**±0.023)

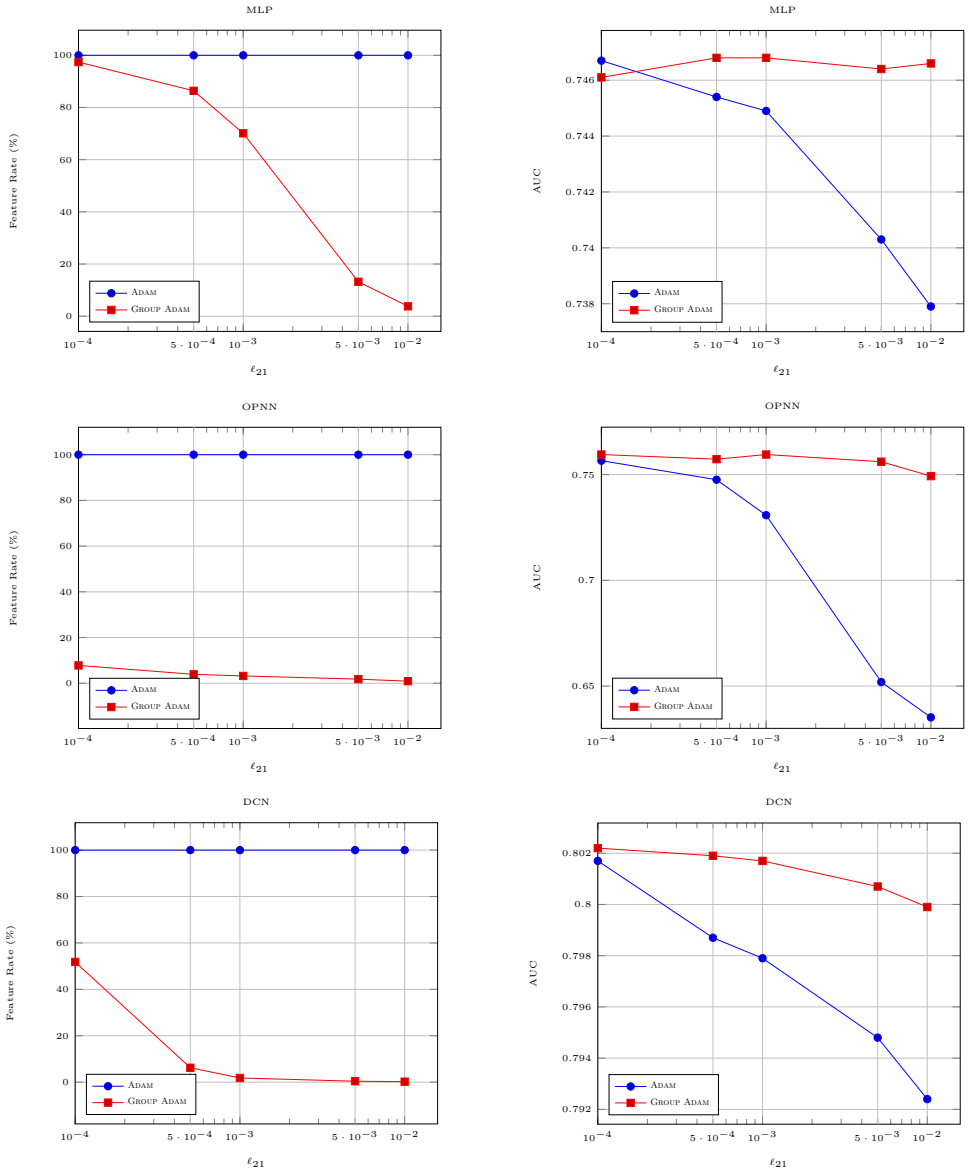

Figure 1: The feature rate and AUC across different regularized terms ℓ_{21} on two methods. The legend is the optimizers of the two methods. The x-axis is the values of ℓ_{21}. The y-axis is nonzero feature (the embedding vector of the feature is not equal to $\mathbf{0}$) rate in left column, and AUC in right column.