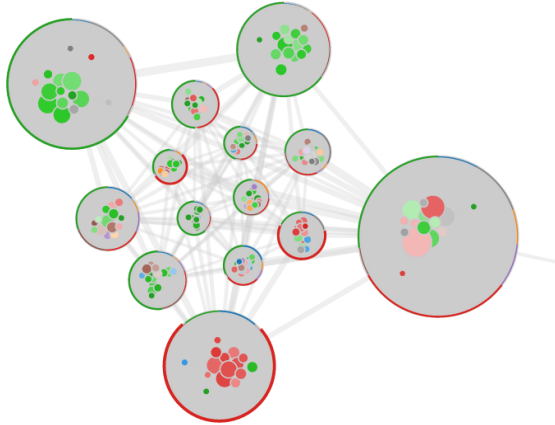


Fast Eigen-Functions Tracking on Dynamic Graphs

Chen Chen and Hanghang Tong



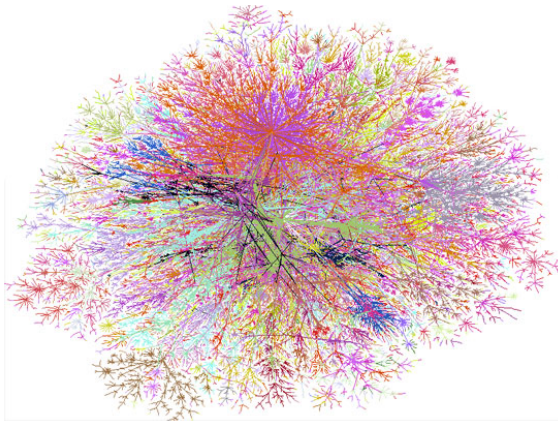
Graphs are Ubiquitous!



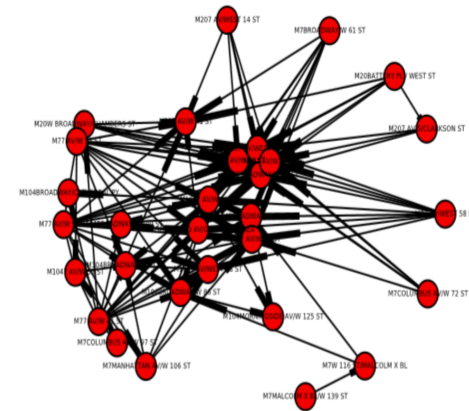
Collaboration Network



Hospital Network



Autonomous Network



Transportation Network

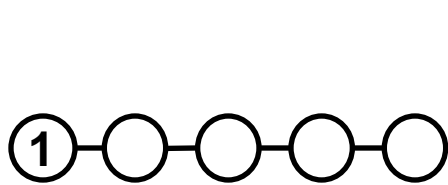
Key Graph Parameters

- P1: Epidemic Threshold (Propagation network)
- P2: Centrality of nodes (All networks)
- P3: Clustering Coefficient (Social network)
- P4: Graph Robustness (Router/Transportation)

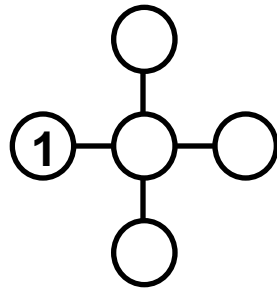
P1: Epidemic Threshold

- **Questions:** How easy is it to spread disease?

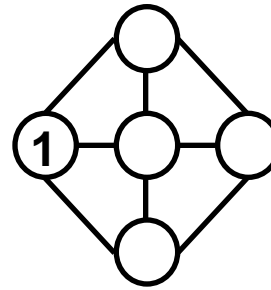
- **Intuition**



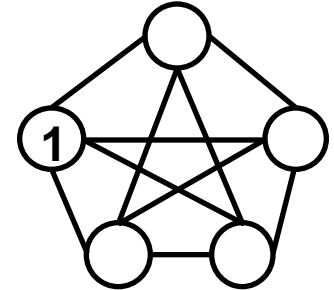
$$\lambda = 1.7$$



$$\lambda = 2.0$$



$$\lambda = 2.9$$



$$\lambda = 4.0$$

- **Solution:** Related to the leading eigenvalue (λ) of the adjacency matrix for **ANY** cascade model [ICDM 2011]

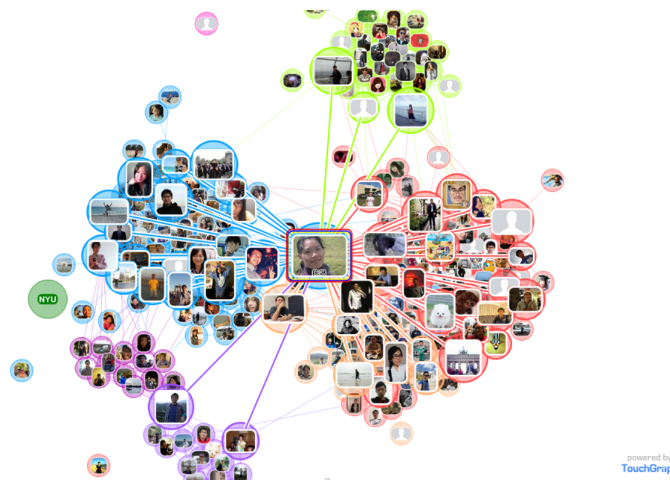
P2: Node Centrality

- **Question:** How important is a node?
- **Intuition:** Having more important friends are considered influential
- **Commonly used:** Eigenvector Centrality

The eigenvector corresponding to the leading eigenvalue ($Au = \lambda u$)

P3: Clustering Coefficient

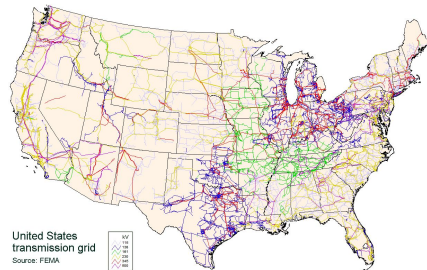
- **Question:** How the nodes in the graph cluster together?
- **Intuition:**



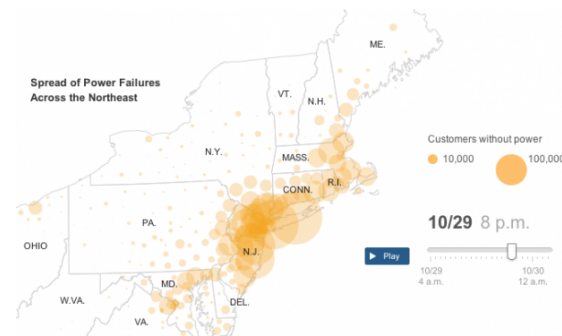
- **Solution:**
$$C = \frac{3 \times \text{number of triangles}}{\text{number of connected triplets}}$$

P4: Graph Robustness

- **Question:** How robust is a graph under external attack?
- **Intuition:**



Power Grid
[wikipedia.com]



Sandy Aftermath
[forbes.com]

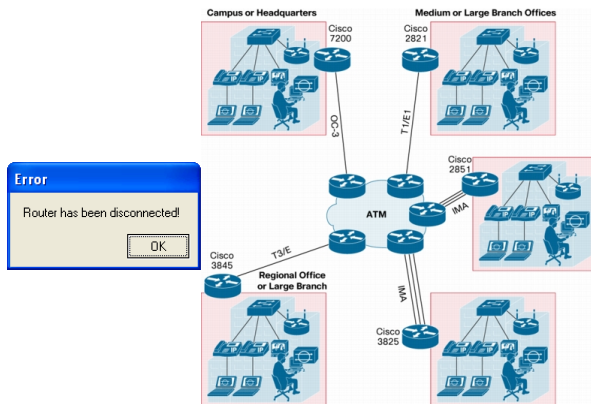
- **Solution:**
$$S(G) = \ln\left(\frac{1}{k} \sum_{i=1}^k e^{\lambda_i}\right)$$
 [SDM2014]

Challenge: Graphs are Dynamic!



Social Networks

Propagation Networks



Router Networks
[www.cisco.com]

Transportation Networks
[www.mapofworld.com]

How to track key graph parameters?

Eigen-Function Tracking

- Q1. Track key graph parameters
- Q2. Estimate the error of tracking algorithms
- Q3. Analyze attribution for drastic changes

Roadmap


- ✓ ■ Motivations
- ➡ ■ Q1: Efficient tracking algorithms
 - Q2: Error estimation methods
 - Q3: Attribution analysis
 - Conclusion

Key Graph Parameters

- Observations: P1-P4 are all eigen-functions

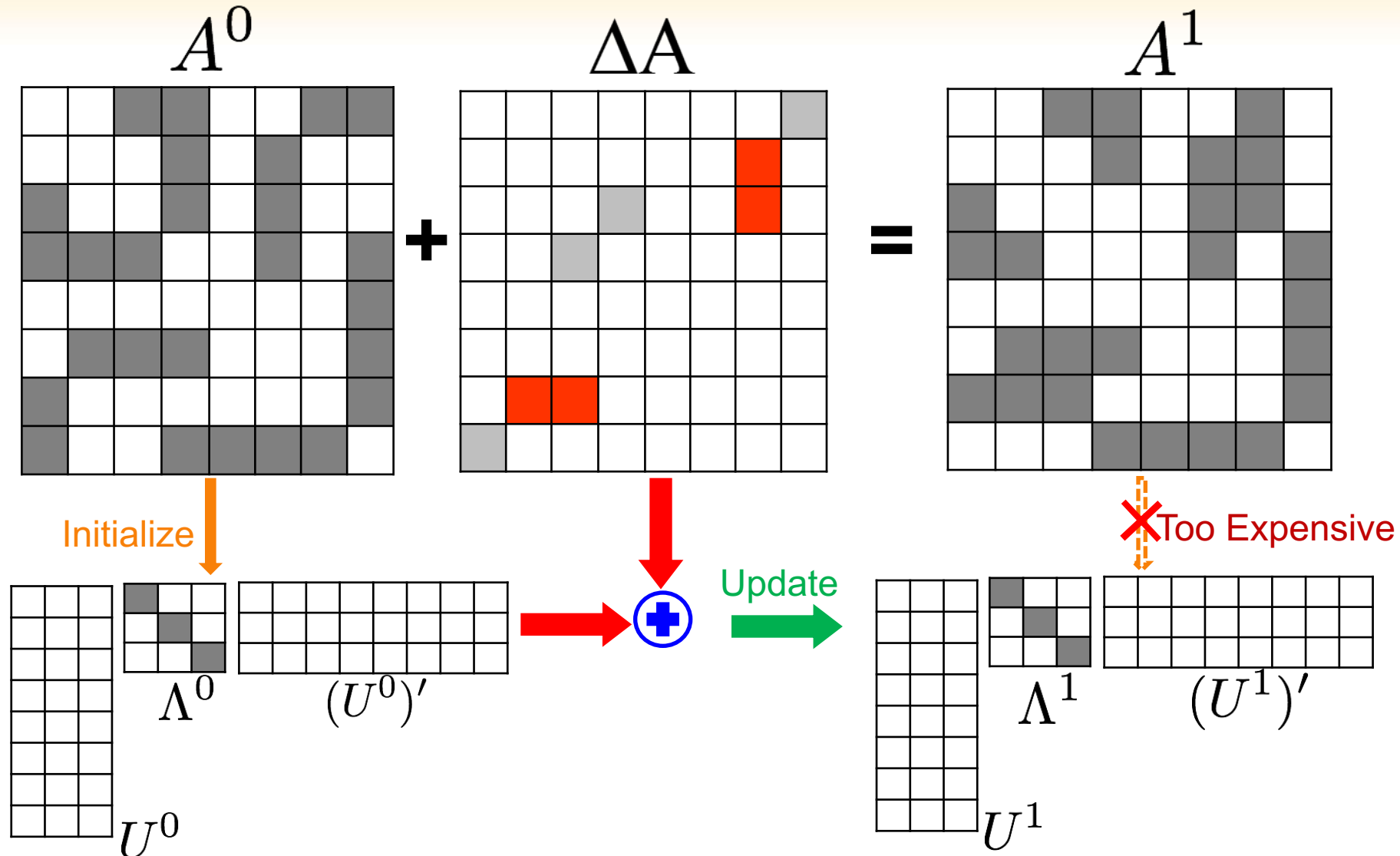
$$f((\Lambda_k, U_k)) = \begin{cases} \lambda_1 & \text{P1. Epidemic Threshold} \\ u_1 & \text{P2. Eigenvector Centrality} \\ \Delta(G) = \frac{1}{6} \sum_{i=1}^k \lambda_i^3 & \text{P3. Clustering Coefficient} \\ & \text{(Triangles)} \\ S(G) = \ln\left(\frac{1}{k} \sum_{i=1}^k e^{\lambda_i}\right) & \text{P4. Robustness Score} \end{cases}$$

Goal: Tracking Top Eigen-Pairs

- Method 1.
 - Calculate (Λ_k, U_k) **from scratch** whenever the structure changes
 - Lanczos algorithm $O(T(mk + nk^2))$ 

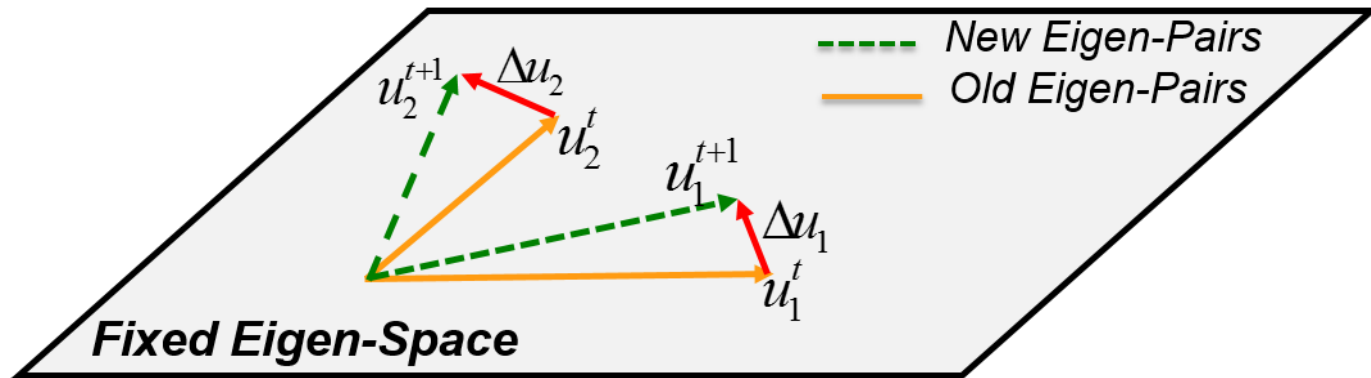
Too costly for fast-changing large graphs!

Key Idea



Key Idea: Incrementally Update

- Intuition:



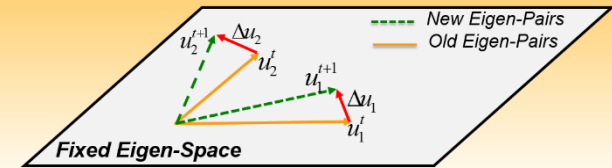
- Solution: Matrix Perturbation Theory

$$\begin{aligned}
 A^{t+1} u_1^{t+1} &= \lambda_1^{t+1} u_1^{t+1} & (A + \Delta A)(u_1 + \Delta u_1) &= (\lambda_1 + \Delta \lambda_1)(u_1 + \Delta u_1) \\
 A^{t+1} u_2^{t+1} &= \lambda_2^{t+1} u_2^{t+1} & (A + \Delta A)(u_2 + \Delta u_2) &= (\lambda_2 + \Delta \lambda_2)(u_2 + \Delta u_2)
 \end{aligned}$$

$A^{t+1} = A^t + \Delta A$
 $\lambda^{t+1} = \lambda^t + \Delta \lambda$
 $u^{t+1} = u^t + \Delta u$

Time stamp omitted for brevity.

Details: Step 1



$$(A + \Delta A)(u_1 + \Delta u_1) = (\lambda_1 + \Delta \lambda_1)(u_1 + \Delta u_1)$$

$$(A + \Delta A)(u_2 + \Delta u_2) = (\lambda_2 + \Delta \lambda_2)(u_2 + \Delta u_2)$$

$$Au_1 = \lambda_1 u_1 \quad Au_2 = \lambda_2 u_2$$

$$A\Delta u_1 + \Delta Au_1 + \Delta A\Delta u_1 = \lambda_1 \Delta u_1 + \Delta \lambda_1 u_1 + \Delta \lambda_1 \Delta u_1$$

$$A\Delta u_2 + \Delta Au_2 + \Delta A\Delta u_2 = \lambda_2 \Delta u_2 + \Delta \lambda_2 u_2 + \Delta \lambda_2 \Delta u_2$$

First order perturbation terms

High order perturbation terms

Challenge: two equations with four variables $\Delta \lambda_1$ $\Delta \lambda_2$ Δu_1 Δu_2

Solution: Introduce additional constraints and assumptions

$$u_i' u_i = 1 \quad u_i' u_j = 0 \quad (i \neq j)$$

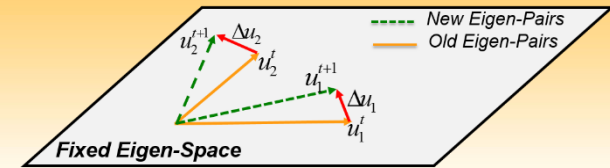
Constraints

$$\Delta u_1 = \alpha_{11} u_1 + \alpha_{12} u_2 \quad \Delta \lambda_i \ll \lambda_i$$

$$\Delta u_2 = \alpha_{21} u_1 + \alpha_{22} u_2 \quad \Delta u_i \ll u_i$$

Assumptions

Details: Estimate $\Delta\lambda_i$



- Discard high order term

$$A\Delta u_i + \Delta A u_i + \cancel{\Delta A \Delta u_i} = \lambda_i \Delta u_i + \Delta \lambda_i u_i + \cancel{\Delta \lambda_i \Delta u_i} \quad (1)$$

$$\Delta \lambda_i \ll \lambda_i, \Delta u_i \ll u_i$$

$$A\Delta u_i + \Delta A u_i = \lambda_i \Delta u_i + \Delta \lambda_i u_i \quad (2)$$

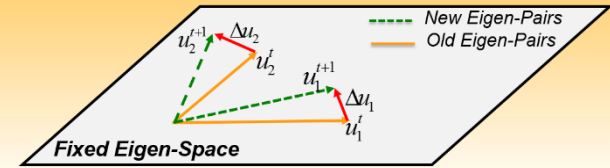
Multiply u_i' on both side

$$u_i' A \Delta u_i + u_i' \Delta A u_i = u_i' \lambda_i \Delta u_i + u_i' \Delta \lambda_i u_i \quad (3)$$

$$A u_i = \lambda_i u_i, u_i' u_i = 1$$

$$\Delta \lambda_i = u_i' \Delta A u_i$$

Estimate Δu_i (Option 1)



$$A\Delta u_i + \Delta A u_i = \lambda_i \Delta u_i + \Delta \lambda_i u_i \quad (\text{Discard high order})$$

↓ Multiply u_j' on both side 1

$$u_j' A \Delta u_i + u_j' \Delta A u_i = u_j' \lambda_i \Delta u_i + u_j' \Delta \lambda_i u_i \quad 2$$

↓ $Au_j = \lambda_j u_j, u_j' u_i = 0$ 3

$$u_j' \Delta A u_i = (\lambda_i - \lambda_j) u_j' \Delta u_i$$

(Trip-Basic)

↓ $\Delta u_i = \sum_{p=1}^k \alpha_{ip} u_p$ 4

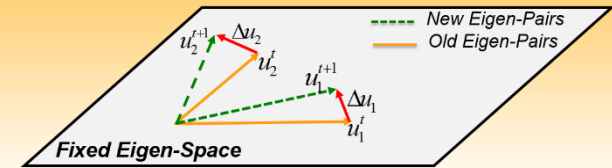
$$\alpha_{ij} = \frac{u_j' \Delta A u_i}{\lambda_i - \lambda_j} \quad \leftarrow u_j' \Delta A u_i = (\lambda_i - \lambda_j) \left(\sum_{p=1, p \neq j}^k \alpha_{ip} u_j' u_p + \alpha_{ij} u_j' u_j \right)$$

$$u_i' u_j = 0, u_i' u_i = 1$$

Time Complexity: $O(Tk^2(s+n))$ ($s = |\Delta A|$)

Lanczos: $O(T(mk + nk^2))$

Estimate Δu_i (Option 2)



- Keep high order perturbation terms

$$A\Delta u_i + \Delta A u_i + \underline{\Delta A \Delta u_i} = \lambda_i \Delta u_i + \Delta \lambda_i u_i + \underline{\Delta \lambda_i \Delta u_i}$$

$$\Delta \lambda_i = u_i' \Delta A u_i, \Delta u_i = \sum_{j=1}^k \alpha_{ij} u_j$$

(Trip)

$$\alpha_i = (D - \textcircled{X})^{-1} X(:, i) \quad (\alpha_i = [\alpha_{i1}, \alpha_{i2}, \dots, \alpha_{ik}])$$

where $X = U_k' \Delta A U_k$, $D = \text{diag}(\lambda_i + \textcircled{\Delta \lambda_i} - \lambda_j) \quad (j = 1, \dots, k)$

(Trip-Basic)

$$\alpha_{ij} = \frac{u_j' \Delta A u_i}{\lambda_i - \lambda_j} \iff \alpha_i = D^{-1} X(:, i)$$

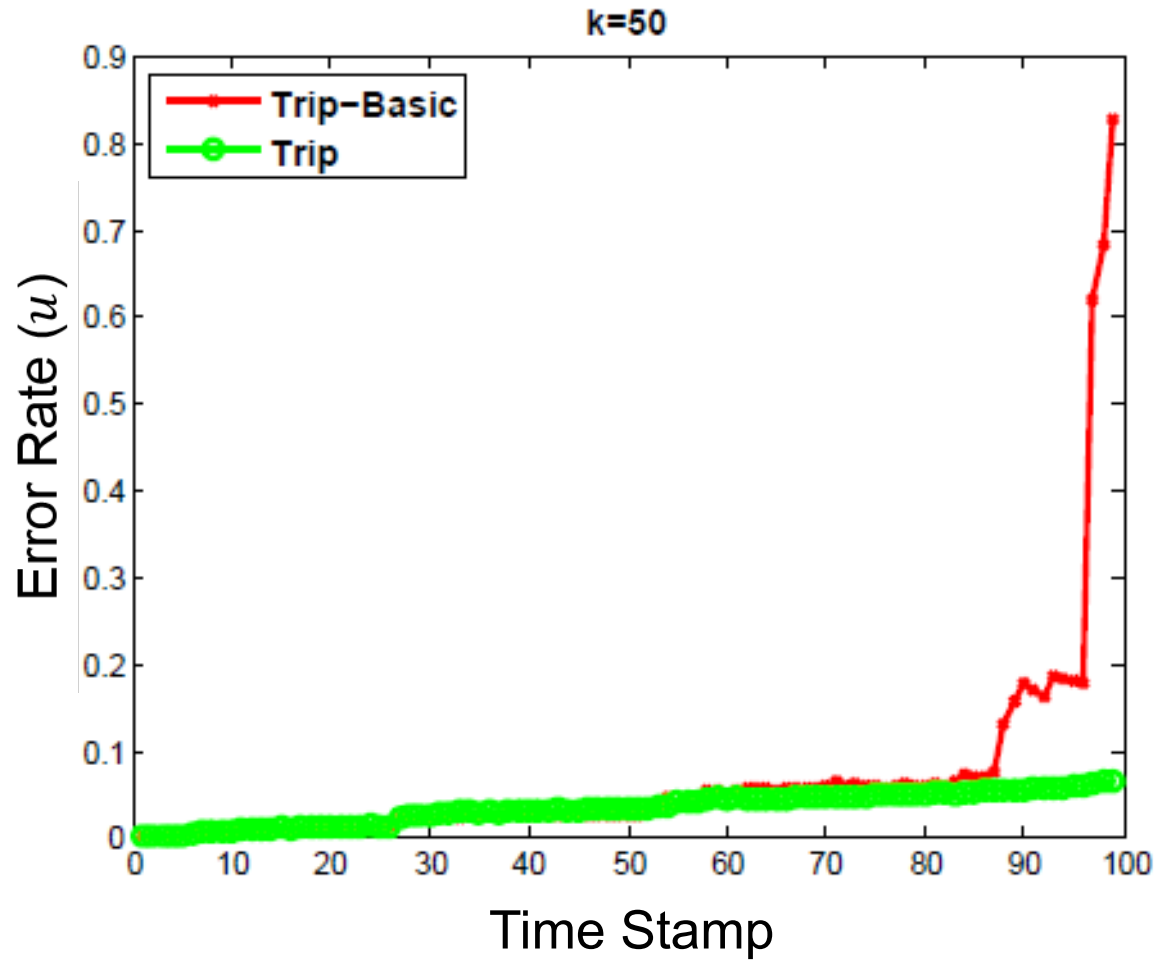
where $X = U_k' \Delta A U_k$, $D = \text{diag}(\lambda_i - \lambda_j) \quad (j = 1, \dots, k)$

Time Complexity: $O(T(k^4 + k^2(n+s)))$ ($s = |\Delta A|$)

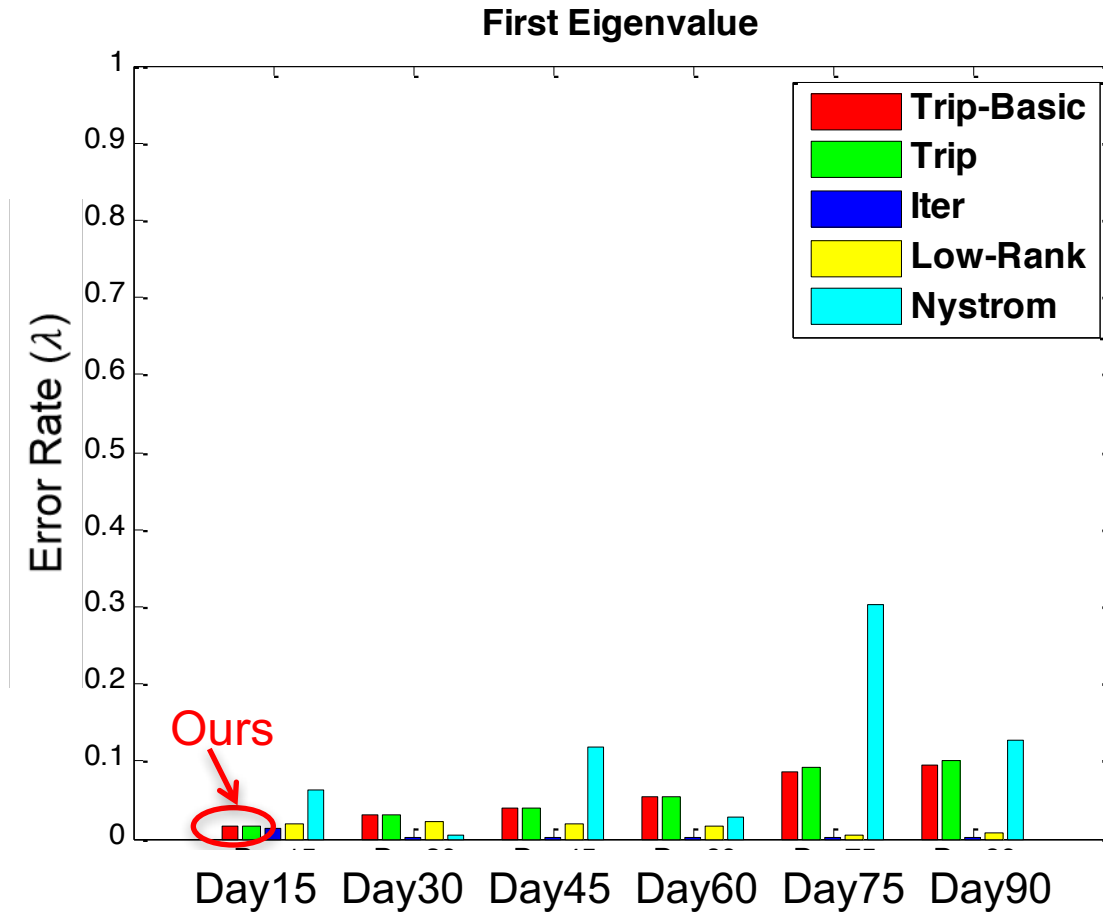
Evaluation

- Data set:
 - Autonomous systems AS-733
(<https://snap.stanford.edu/data/as.html>)
 - 100 days time spans
 - (11/08/1997-02/16/1998)
 - (03/15/1998-06/26/1998)
 - Maximum #nodes = 4,013
 - Maximum #edges = 14,399

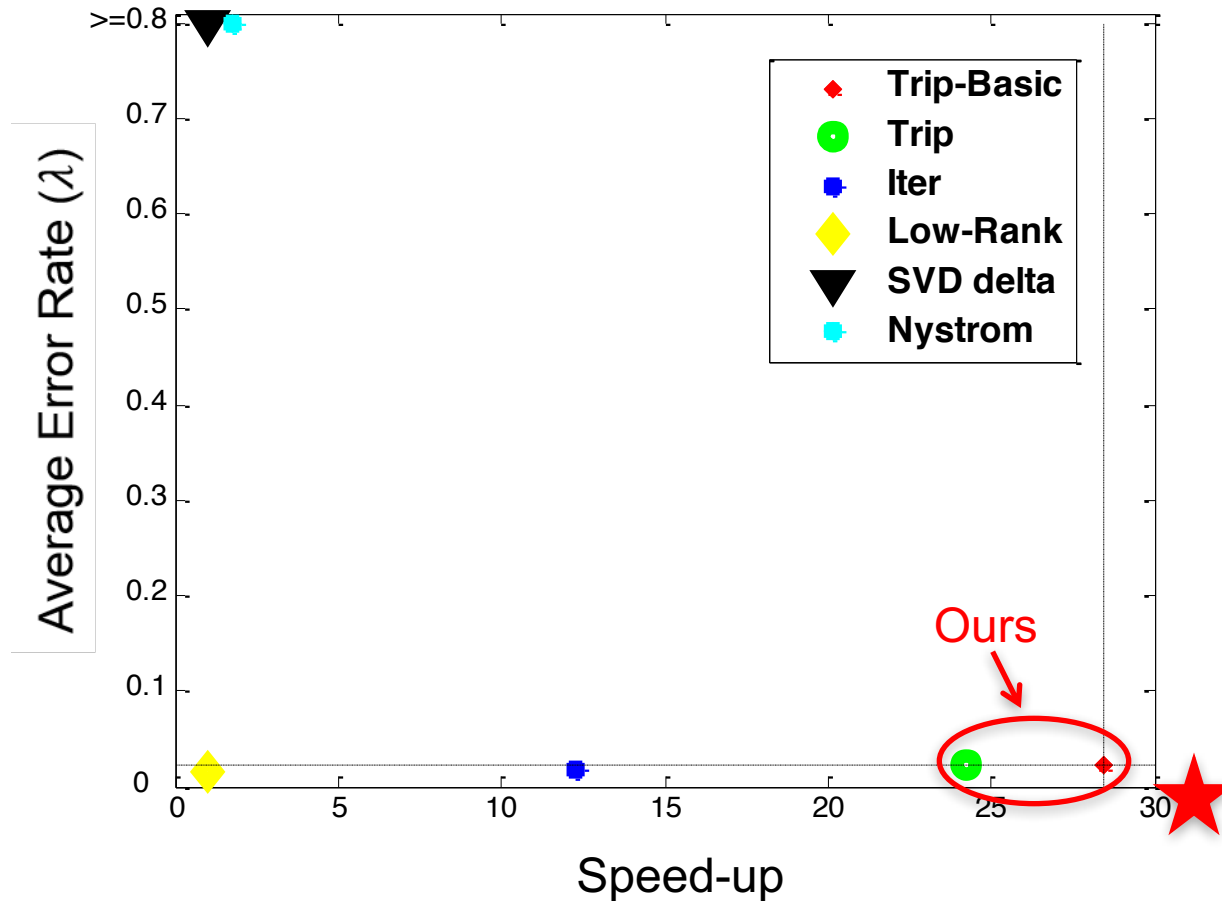
Trip-Basic vs. Trip: Effectiveness



Effectiveness Comparison



Effectiveness vs. Efficiency

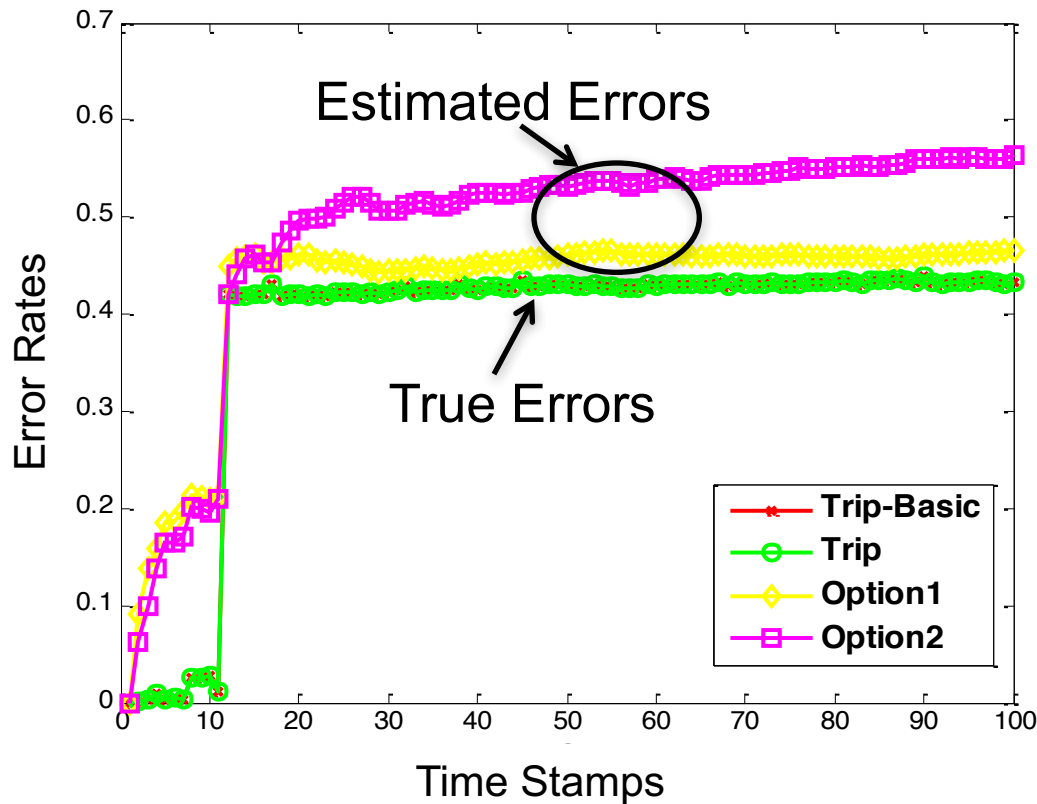


Roadmap

- ✓ ■ Motivations
- ✓ ■ Q1: Efficient tracking algorithms
- ➡ ■ Q2: Error estimation methods
 - Q3: Attribution analysis
 - Conclusion

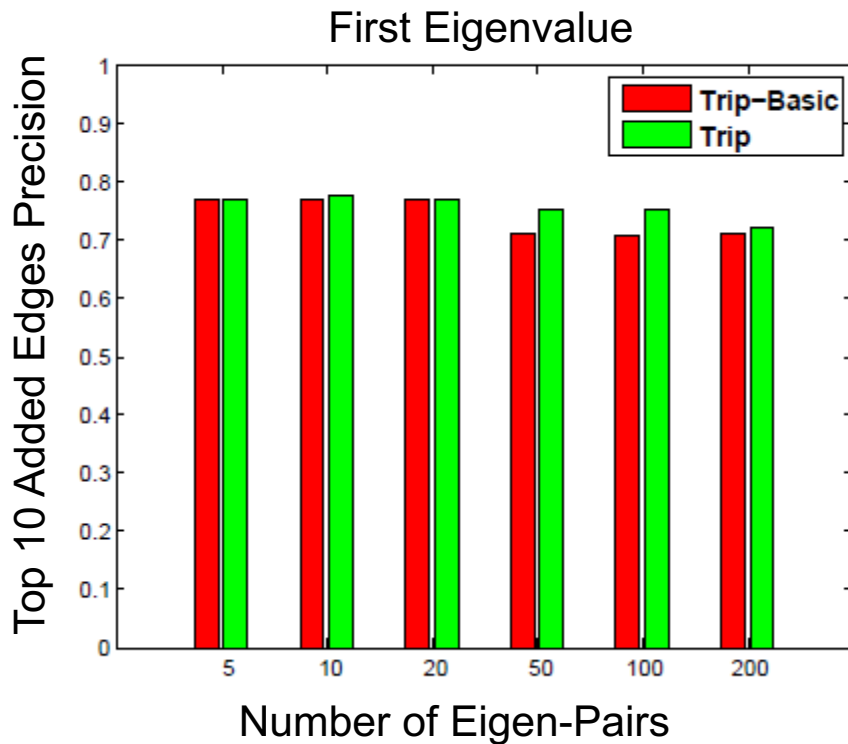
Q2.Error Estimation

- Setting: $c_1 = 0.005, c_2 = 0.025$

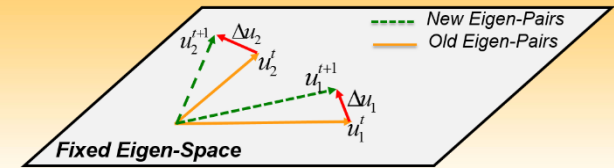


Q3. Attribution Analysis

■ Precision (Edge Addition)



Conclusion



- Goal: Tracking key graph parameters
- Solutions:
 - Key idea:
 - Fixed eigen-space, Matrix perturbation theory
 - Algorithms: Trip-Basic, Trip
- More Details:
 - Error Estimation
 - Attribution Analysis