

# Distance-Sensitive Hashing

Martin Aumüller, Tobias Christiani, Rasmus Pagh, Francesco Silvestri

IT University of Copenhagen & University of Padova

June 11, 2018

PODS 18

*Supported by*



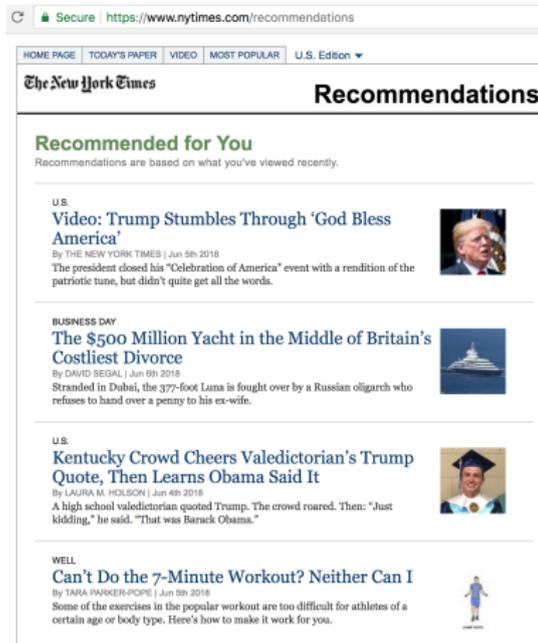
**European Research Council**

Established by the European Commission

**Supporting top researchers  
from anywhere in the world**

# Motivation: Recommender Systems

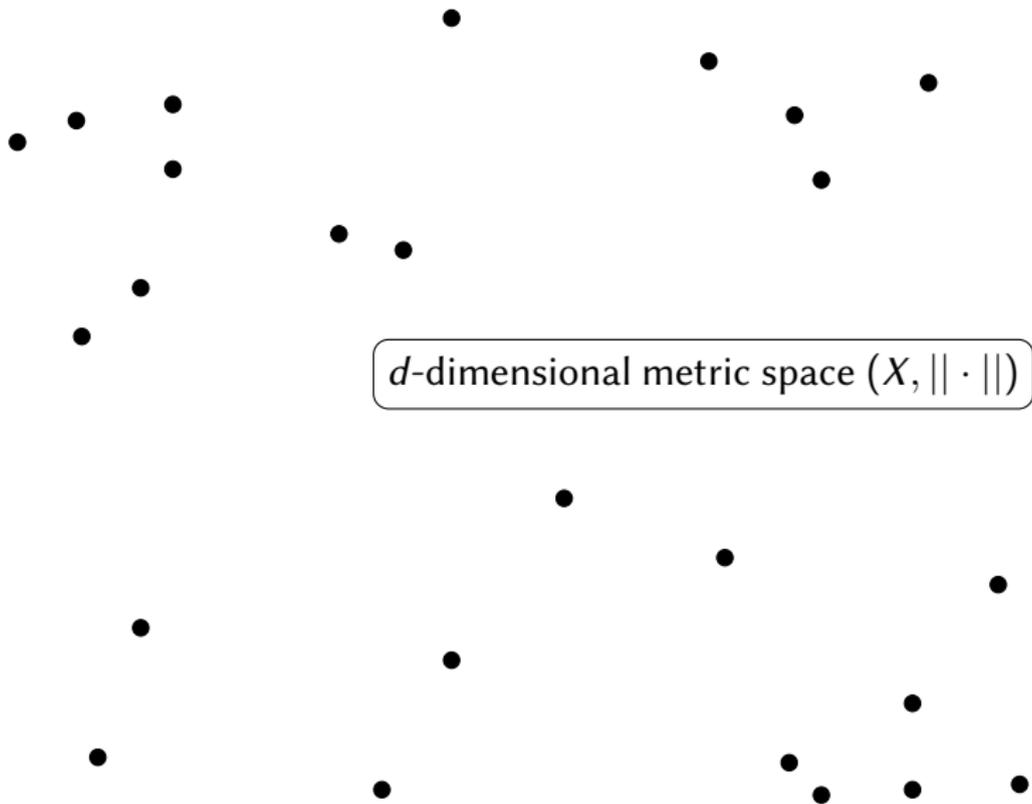
- **Data:** Collection of newspaper articles  $S$
- **Query:** User read article  $x$ , recommend “interesting” other articles from  $S$
- **What is interesting?**
  - ▶ not too close to  $x$
  - ▶ not too far away from  $x$



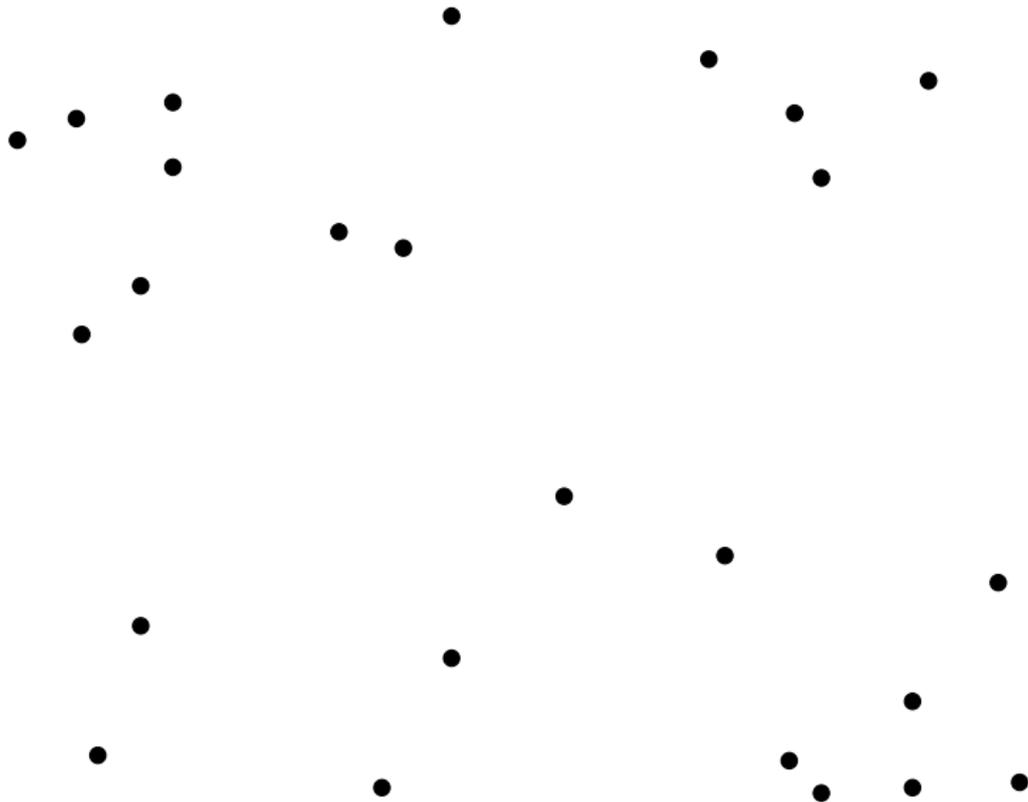
The screenshot shows the 'Recommendations' section of The New York Times website. At the top, there are navigation links for 'HOME PAGE', 'TODAY'S PAPER', 'VIDEO', 'MOST POPULAR', and 'U.S. Edition'. The main heading is 'Recommendations'. Below this, there is a section titled 'Recommended for You' with a sub-note: 'Recommendations are based on what you've viewed recently.' The first recommendation is a video titled 'Video: Trump Stumbles Through 'God Bless America'' by THE NEW YORK TIMES, dated Jun 5th 2018. The second recommendation is an article titled 'The \$500 Million Yacht in the Middle of Britain's Costliest Divorce' by DAVID SEGAL, dated Jun 6th 2018. The third recommendation is an article titled 'Kentucky Crowd Cheers Valetictorian's Trump Quote, Then Learns Obama Said It' by LAURA M. HOLSON, dated Jun 6th 2018. The fourth recommendation is an article titled 'Can't Do the 7-Minute Workout? Neither Can I' by TARA PARKER-POPE, dated Jun 5th 2018. Each recommendation includes a small thumbnail image.

# General setting: Approximate Similarity Search Problems

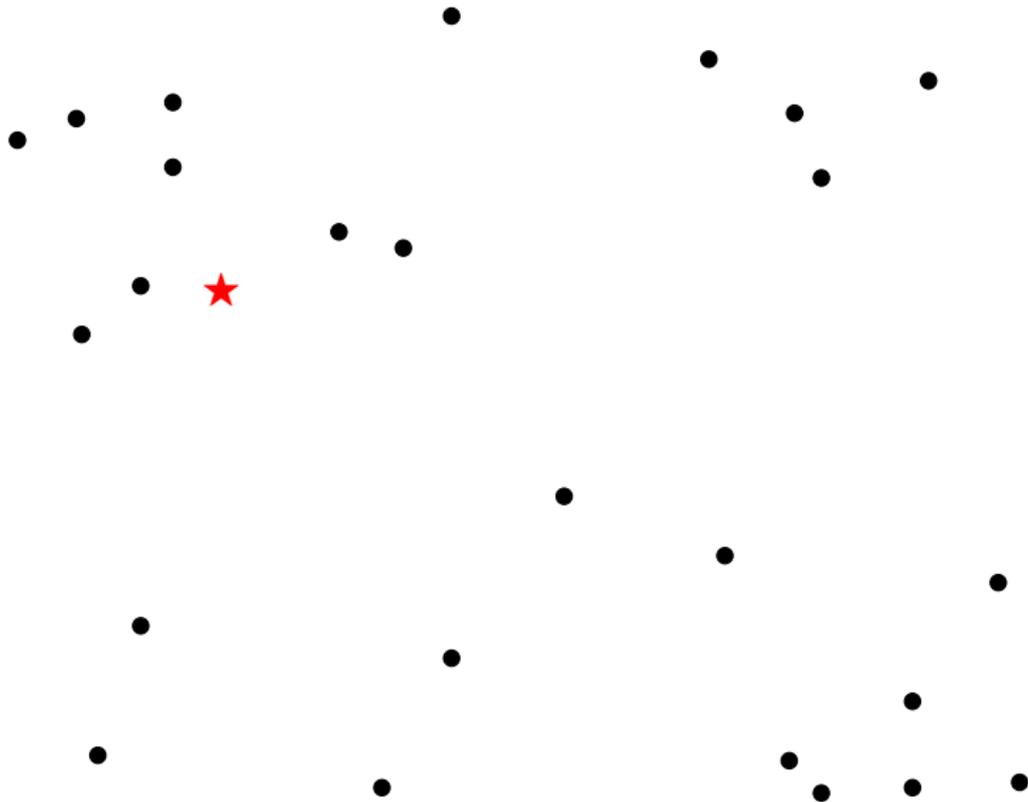
# General setting: Approximate Similarity Search Problems



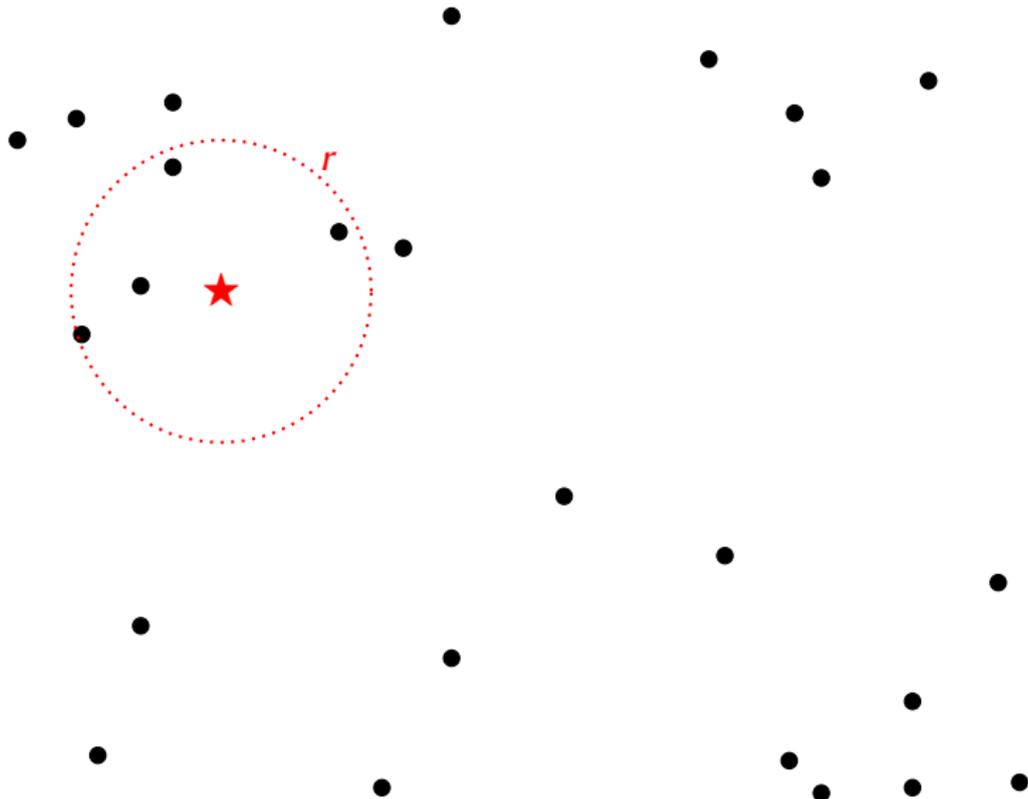
# $(c, r)$ -approximate Annulus Problem



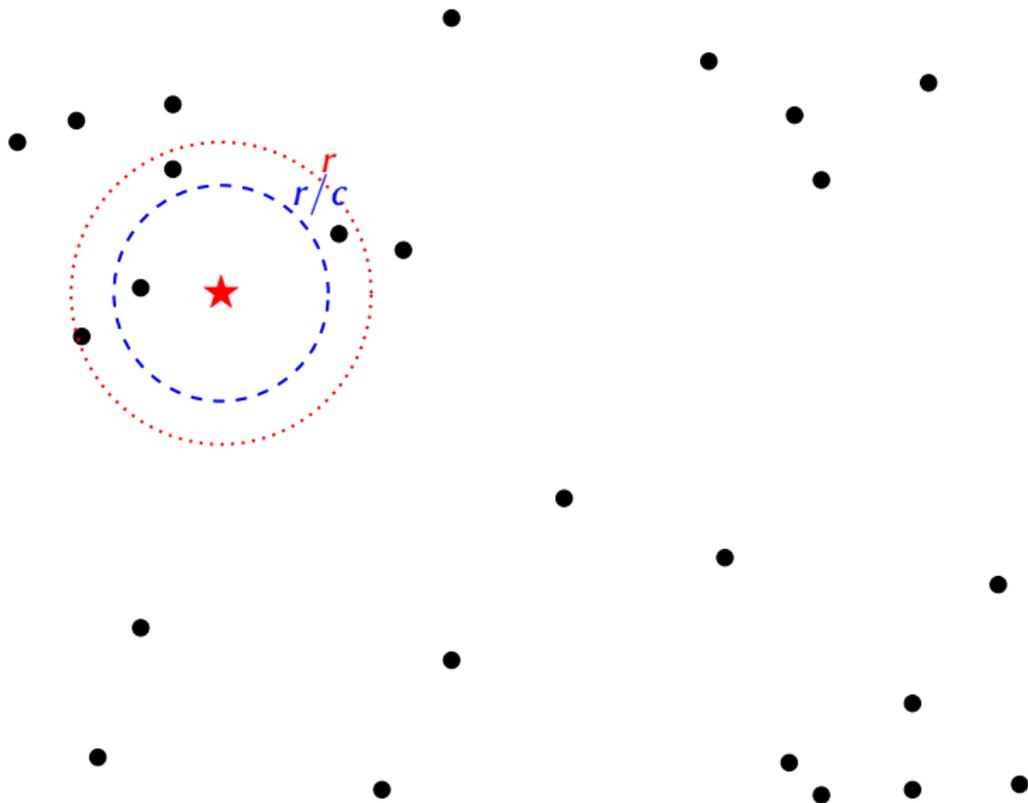
# $(c, r)$ -approximate Annulus Problem



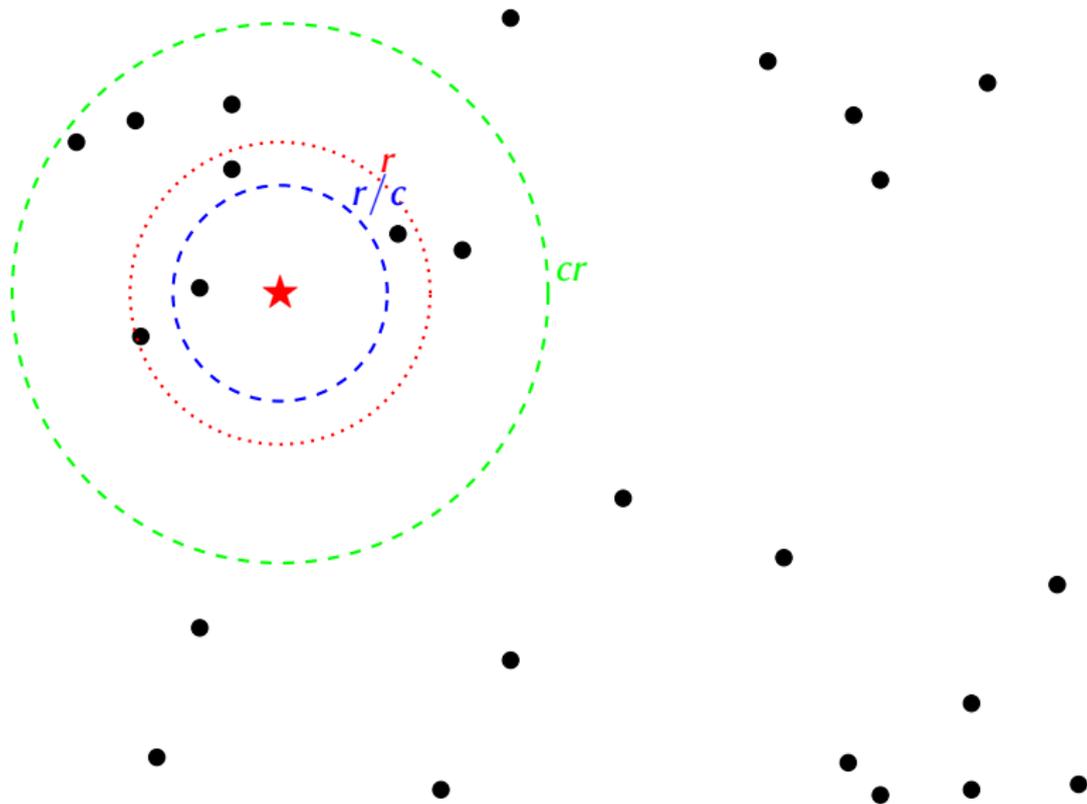
# $(c, r)$ -approximate Annulus Problem



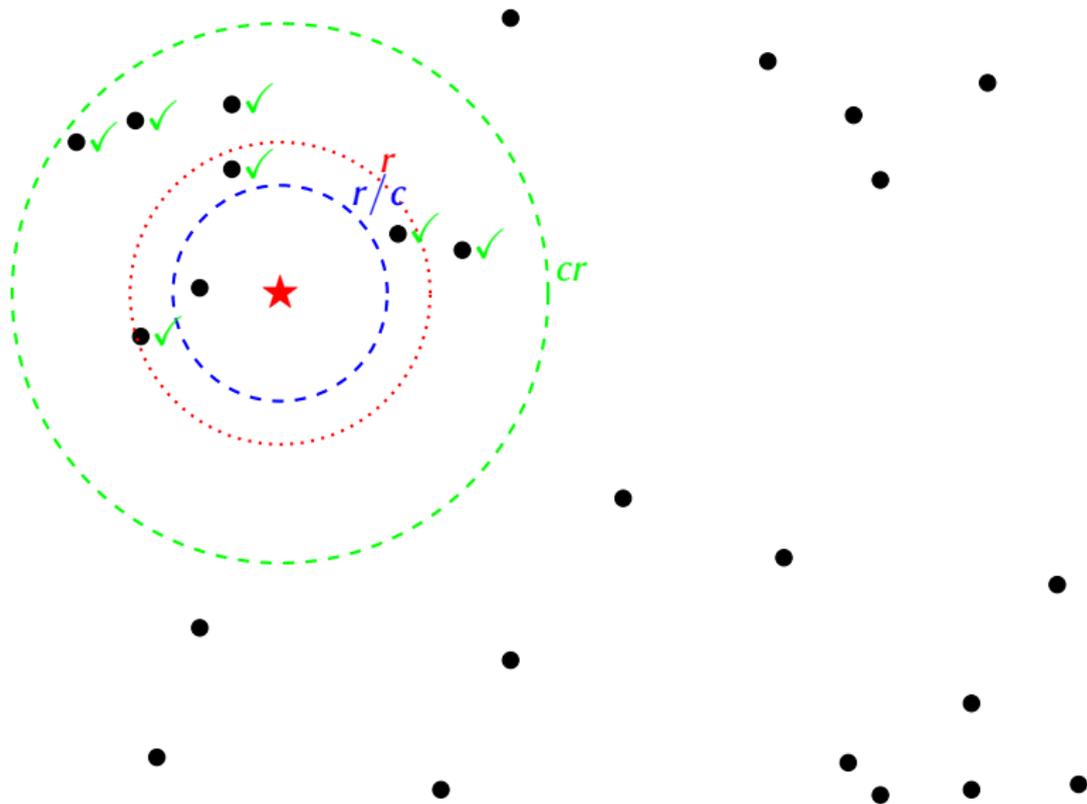
# $(c, r)$ -approximate Annulus Problem

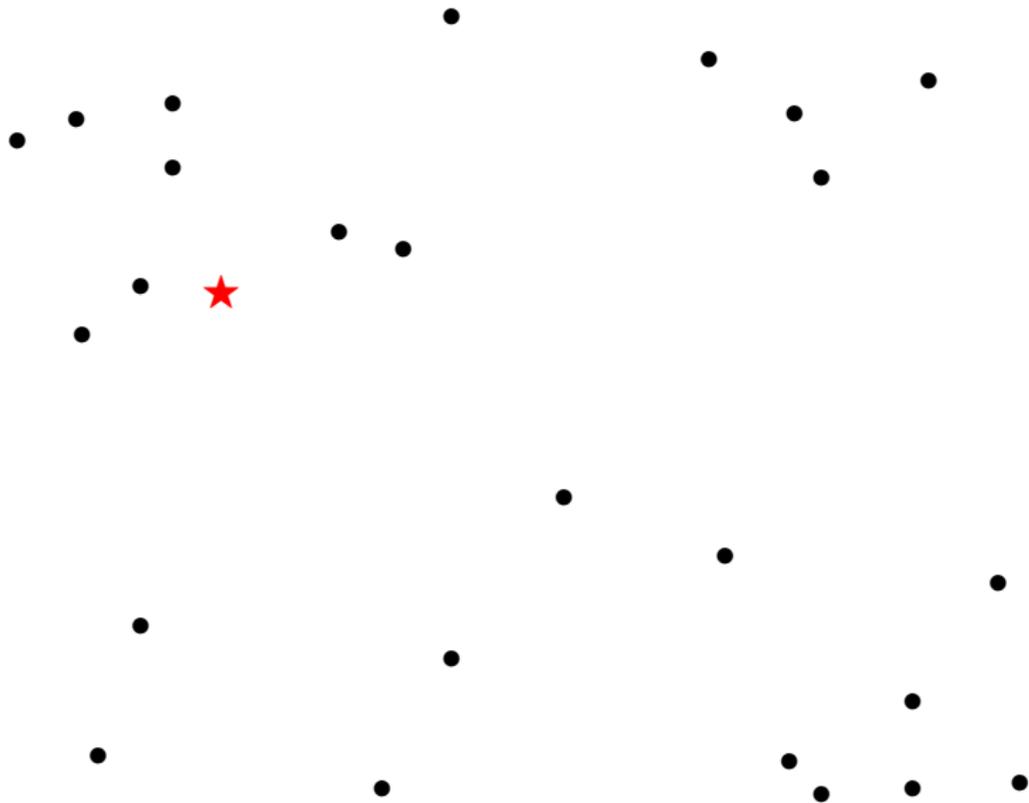


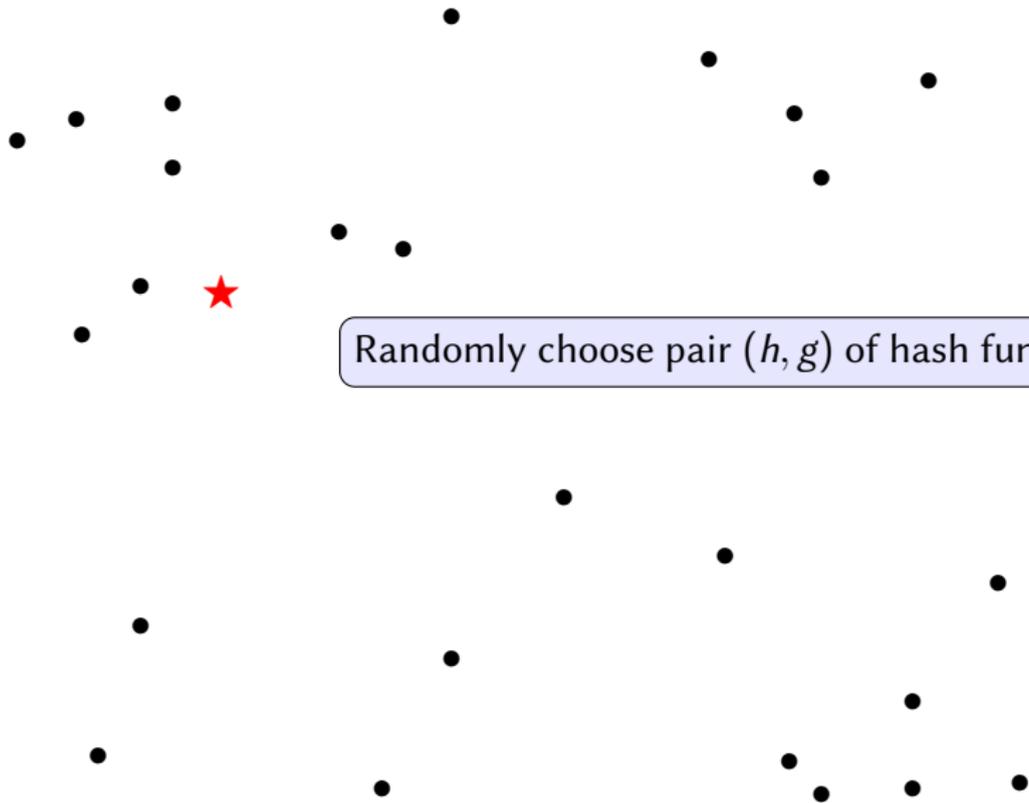
# $(c, r)$ -approximate Annulus Problem



# $(c, r)$ -approximate Annulus Problem





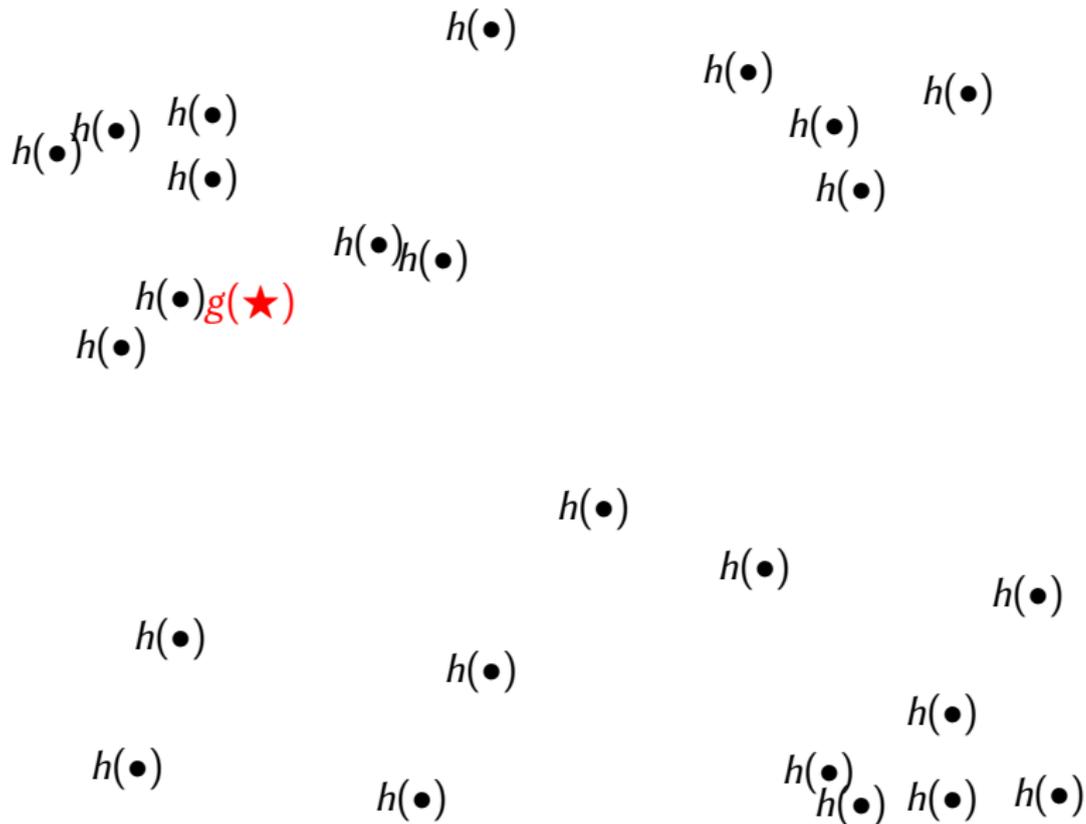


Randomly choose pair  $(h, g)$  of hash functions

$h(\bullet)$   
 $h(\bullet)$   $h(\bullet)$   $h(\bullet)$   
 $h(\bullet)$   $h(\bullet)$   $h(\bullet)$   
 $h(\bullet)$   $h(\bullet)$   
 $h(\bullet)$   $g(\star)$   
 $h(\bullet)$

Randomly choose pair  $(h, g)$  of hash functions

$h(\bullet)$   
 $h(\bullet)$   $h(\bullet)$   $h(\bullet)$   
 $h(\bullet)$   $h(\bullet)$   
 $h(\bullet)$   $h(\bullet)$   
 $h(\bullet)$   $h(\bullet)$   $h(\bullet)$





## Bitsampling for $\{0, 1\}^d$ (IM98)

- **space:**  $\{0, 1\}^d$  – length- $d$  bitstrings
- $\text{dist}(\mathbf{x}, \mathbf{y}) = (\# \text{positions where } \mathbf{x} \text{ and } \mathbf{y} \text{ differ})/d$   
(relative Hamming distance)

**Bitsampling:** Project to random subset of dimensions.

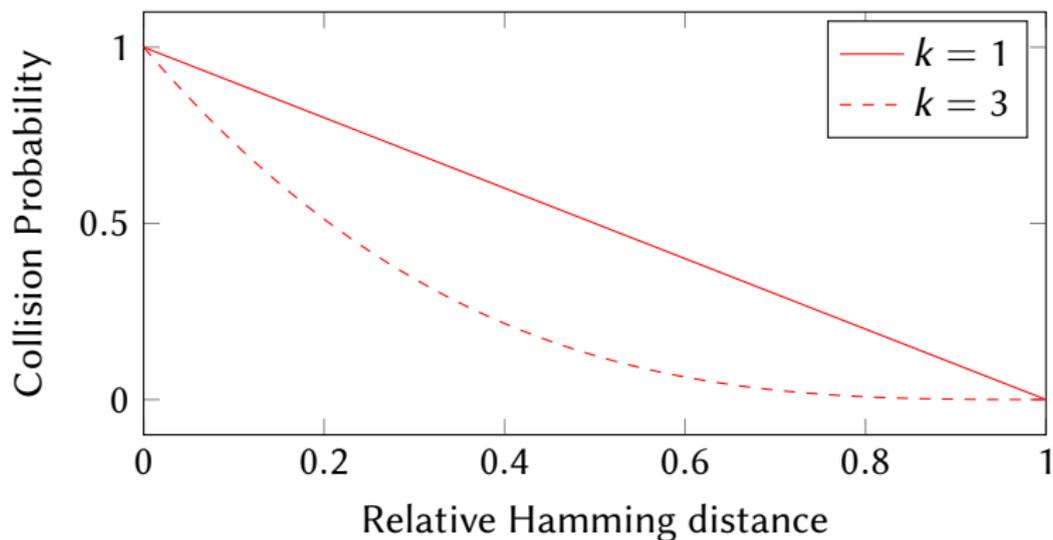
$\mathbf{x}$     00101001010

$\mathbf{y}$     10101100010

$h(\mathbf{x})$     011

$g(\mathbf{y})$     011

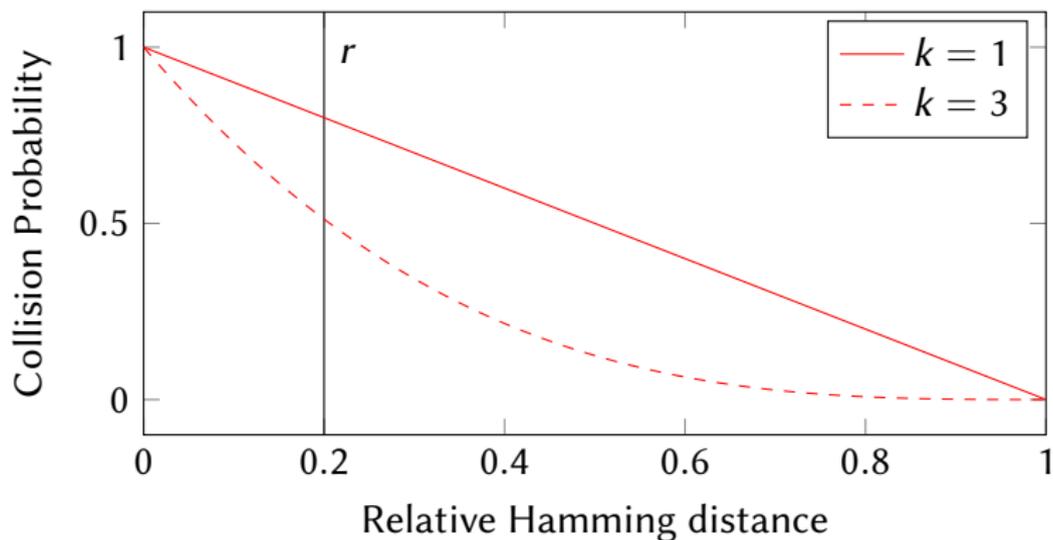
## Bit sampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$  and we sample  $k$  positions, then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^k.$$

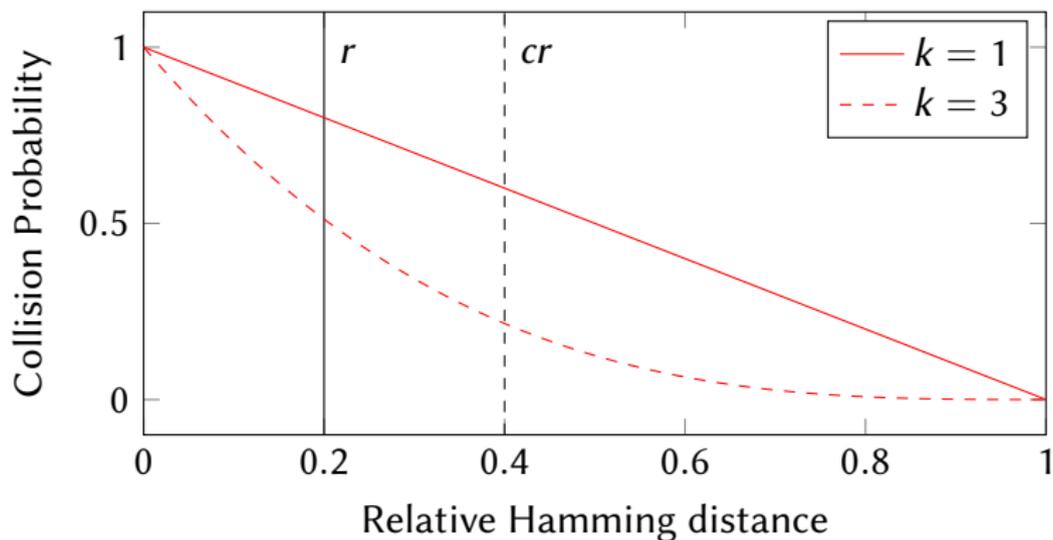
## Bit sampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$  and we sample  $k$  positions, then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^k.$$

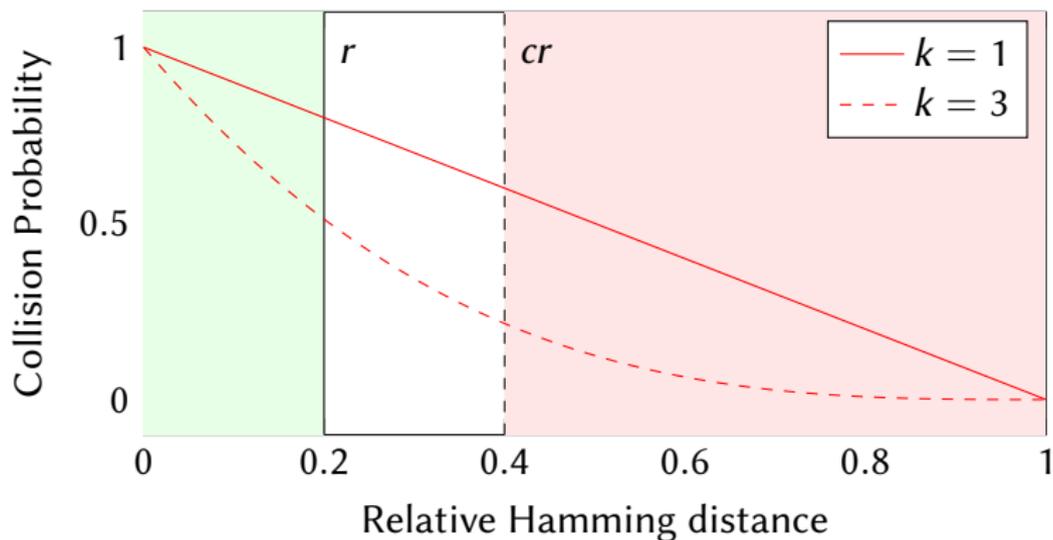
## Bit sampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$  and we sample  $k$  positions, then

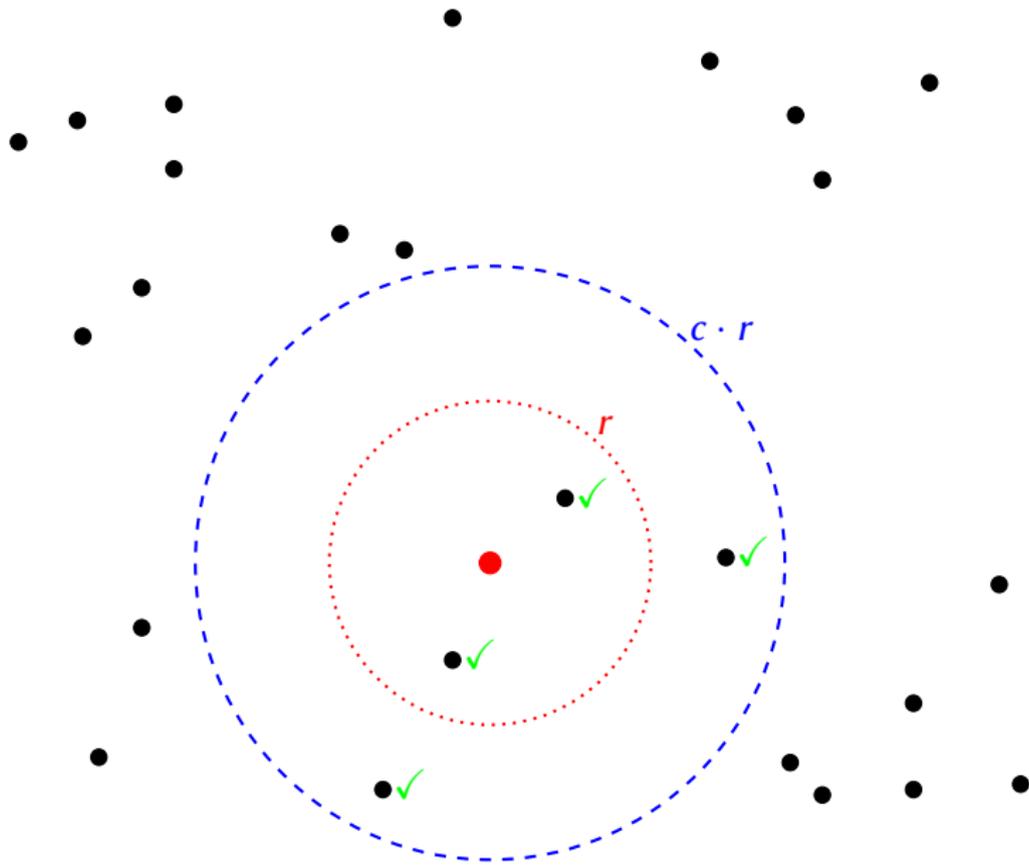
$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^k.$$

## Bit sampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$  and we sample  $k$  positions, then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^k.$$



# “Anti Bitsampling” for $\{0, 1\}^d$

**Anti Bitsampling:** Project to random subset of dimensions, **flip all query hash code bits.**

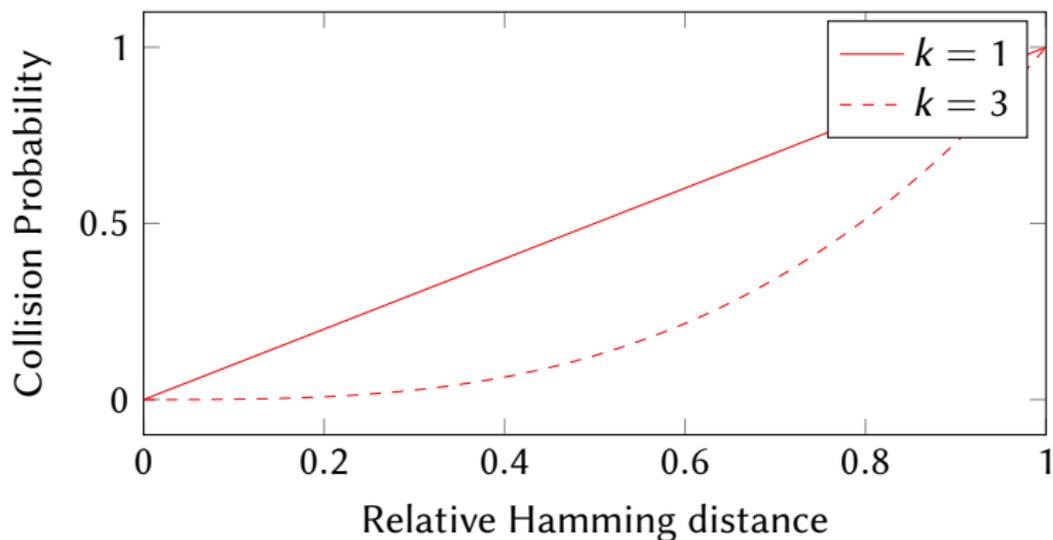
**x**    00101001010

**y**    10101100010

$h(\mathbf{x})$     011

$g(\mathbf{y})$     100

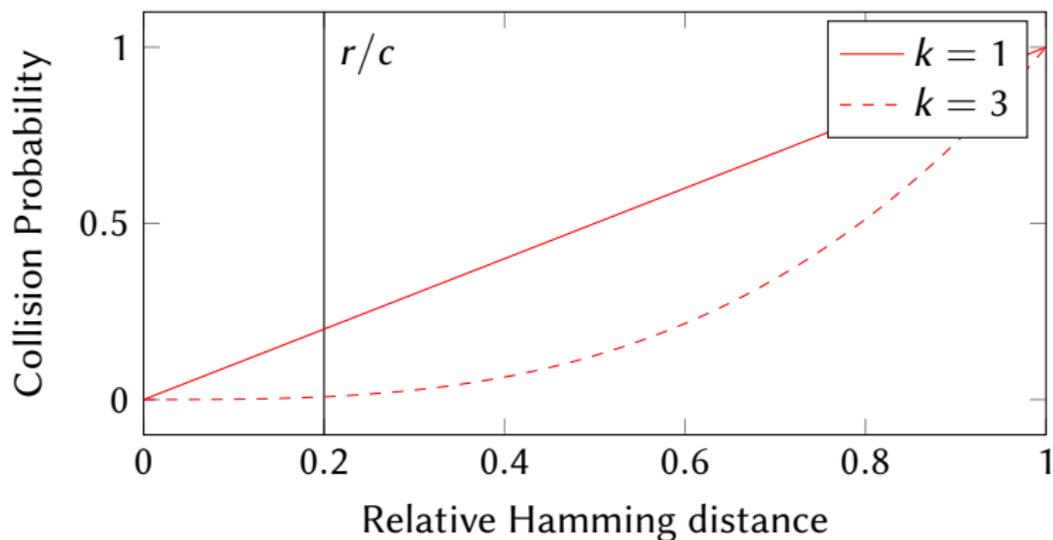
## Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$  and we sample  $k$  positions, then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (r/d)^k.$$

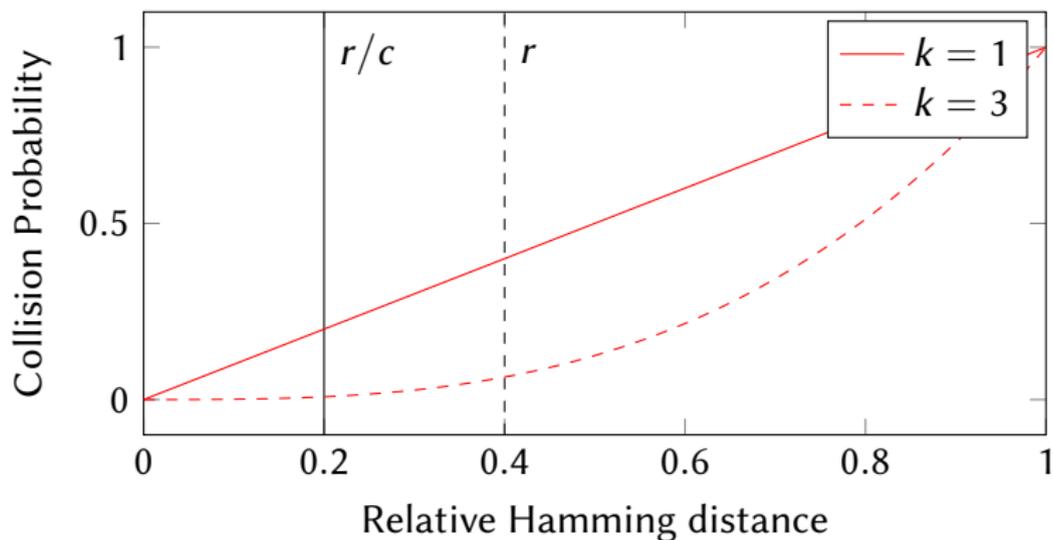
## Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$  and we sample  $k$  positions, then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (r/d)^k.$$

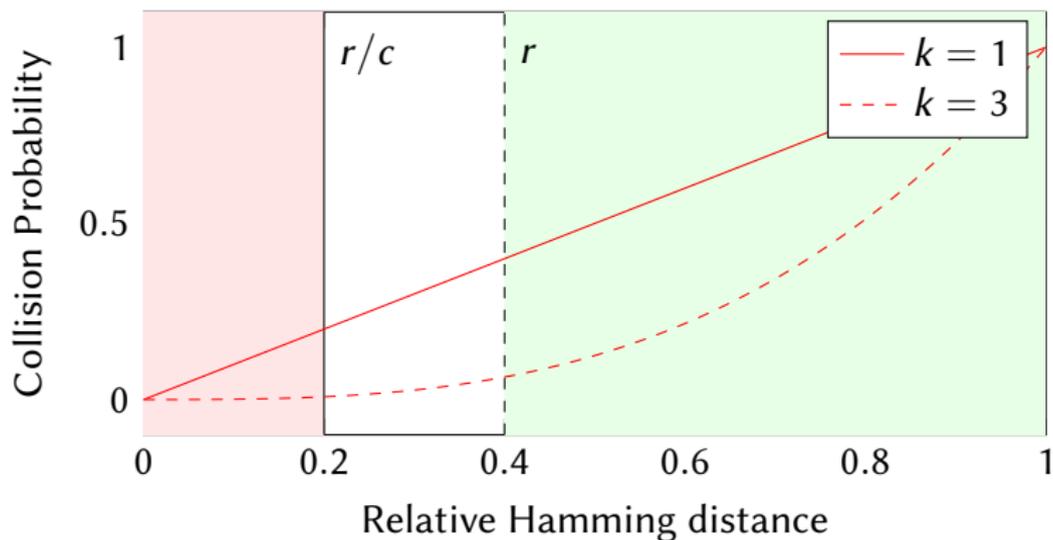
## Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$  and we sample  $k$  positions, then

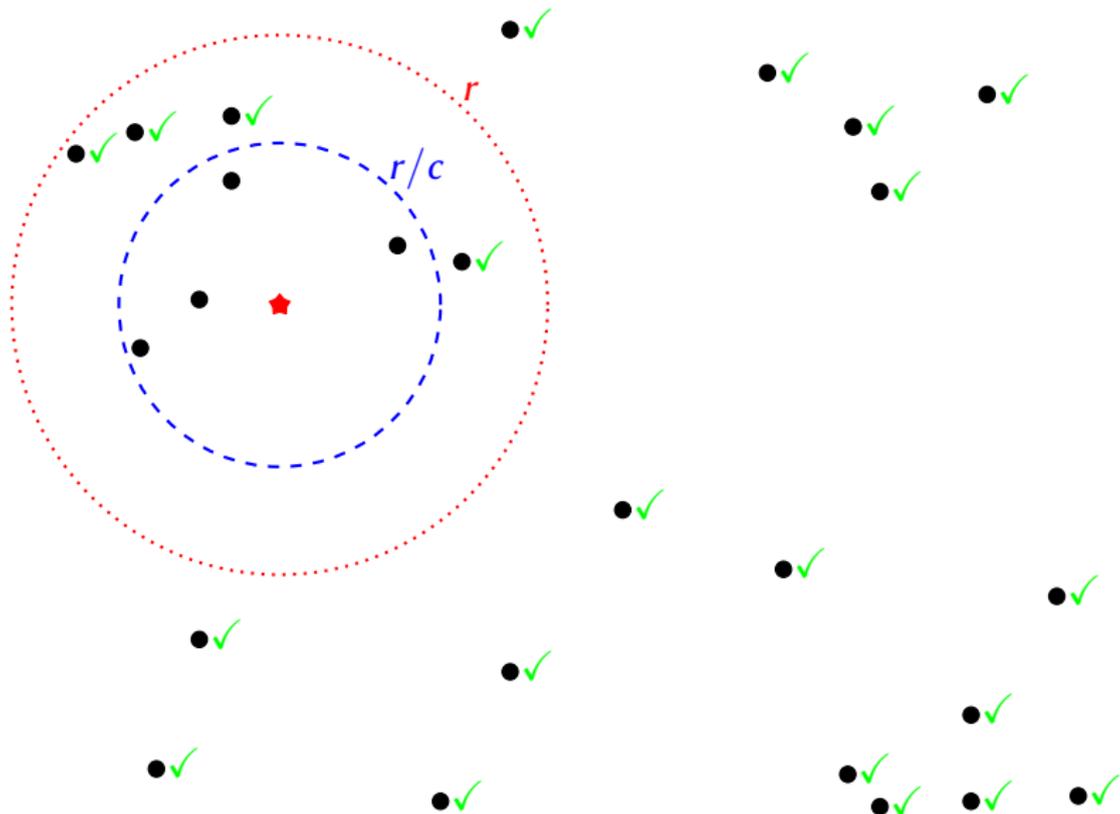
$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (r/d)^k.$$

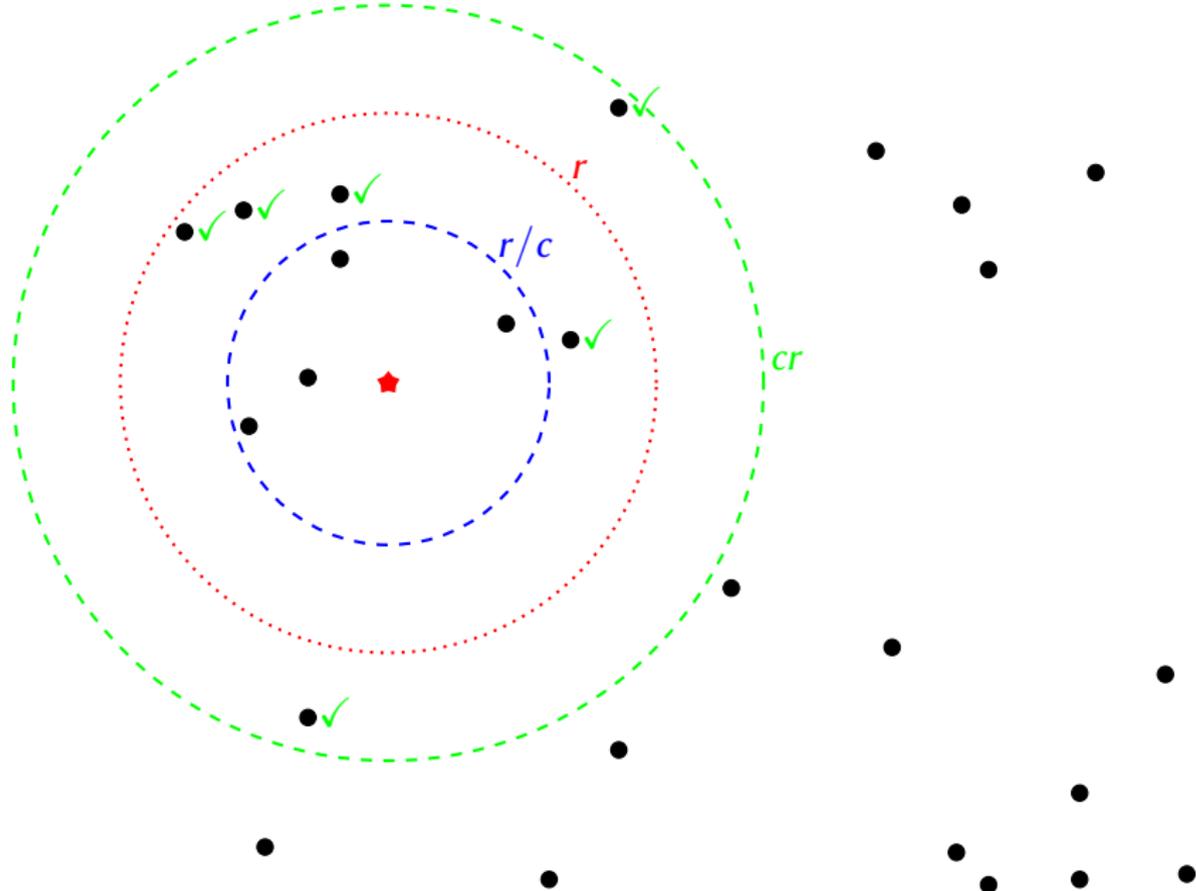
## Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$  and we sample  $k$  positions, then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (r/d)^k.$$





# Bitsampling + Anti Bitsampling for $\{0, 1\}^d$

**Bit + Anti Bitsampling:** Project to random subset of dimensions, **flip some query hash code bits.** (Ex: last two flipped)

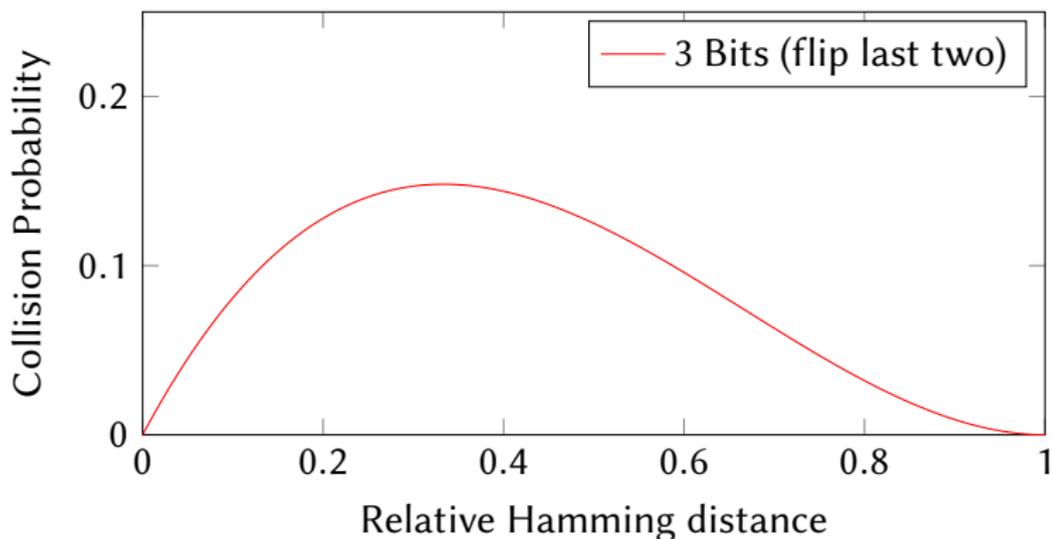
**x**    00101001010

**y**    10101100010

$h(\mathbf{x})$     011

$g(\mathbf{y})$     000

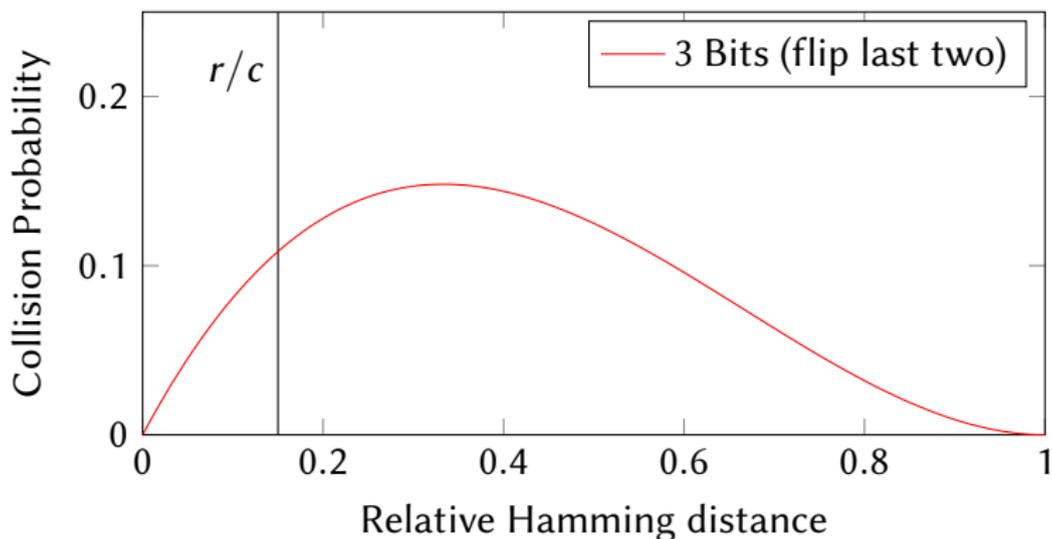
## Bit + Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$ , we sample  $k$  positions and flip the last  $\ell$ , then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^{k-\ell} (r/d)^\ell.$$

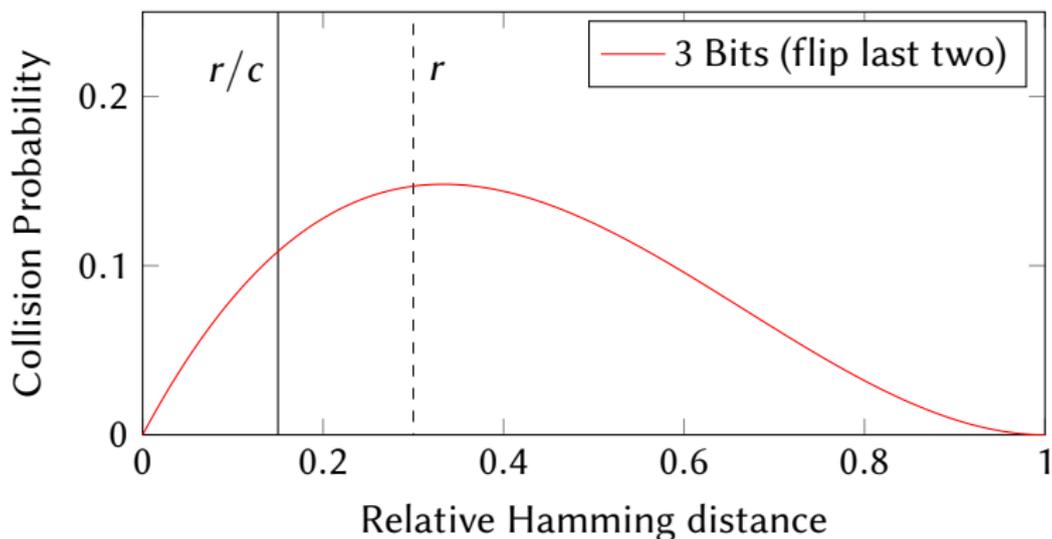
## Bit + Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$ , we sample  $k$  positions and flip the last  $\ell$ , then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^{k-\ell} (r/d)^\ell.$$

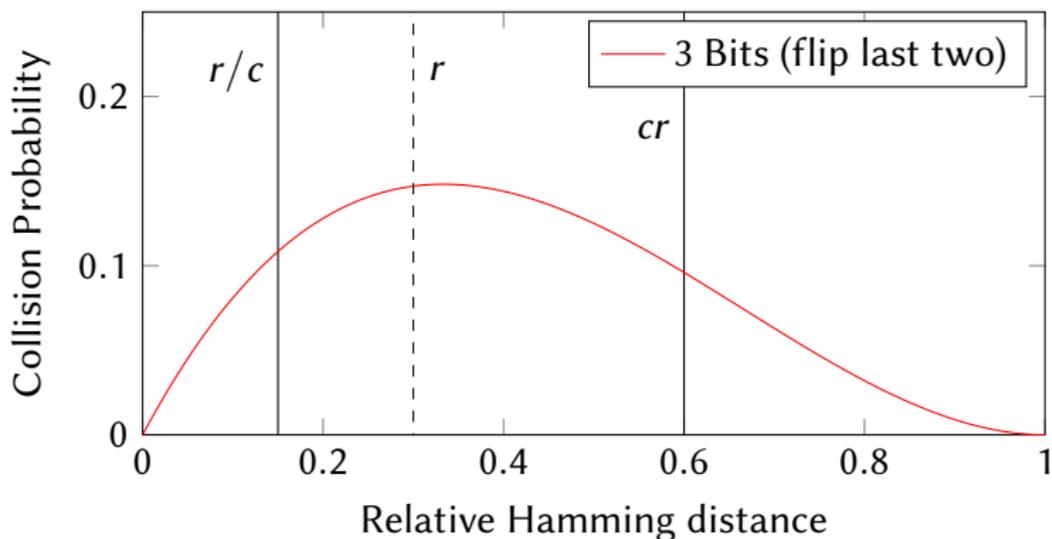
## Bit + Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$ , we sample  $k$  positions and flip the last  $\ell$ , then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^{k-\ell} (r/d)^\ell.$$

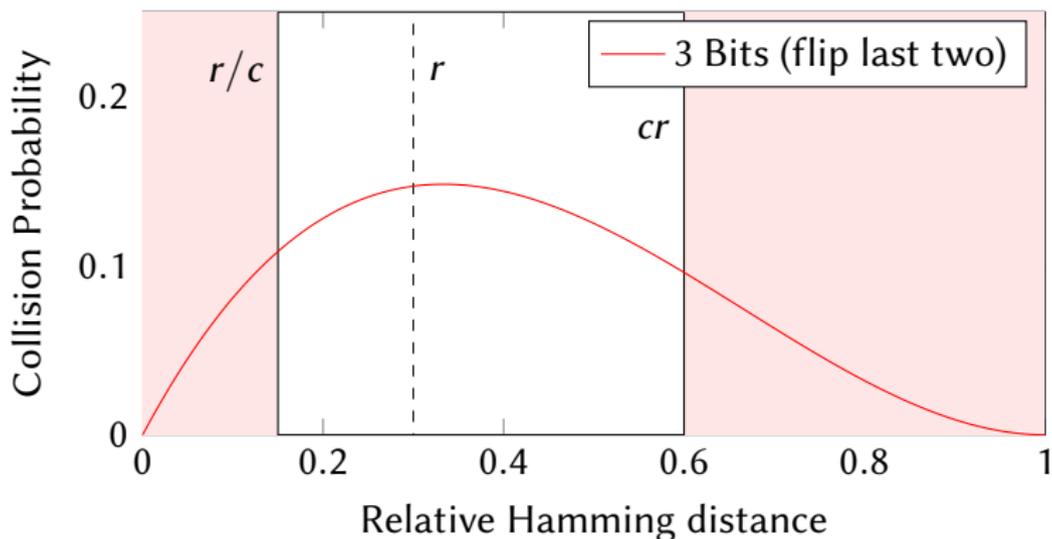
## Bit + Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$ , we sample  $k$  positions and flip the last  $\ell$ , then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^{k-\ell} (r/d)^\ell.$$

## Bit + Anti Bitsampling collision probability



- If  $\text{dist}(\mathbf{x}, \mathbf{y}) = r/d$ , we sample  $k$  positions and flip the last  $\ell$ , then

$$\mathbb{P}(h(\mathbf{x}) = g(\mathbf{y})) = (1 - r/d)^{k-\ell} (r/d)^\ell.$$

# Distance-sensitive Hashing

Assume space  $X$  with distance measure  $\text{dist}: X \times X \rightarrow \mathbb{R}$ .

## Definition

A distribution  $\mathcal{D}$  over pairs of functions  $h, g: X \rightarrow R$  is called *distance-sensitive* with collision probability function (CPF)  $f: \mathbb{R} \rightarrow [0, 1]$  if for each pair  $\mathbf{x}, \mathbf{y} \in X$

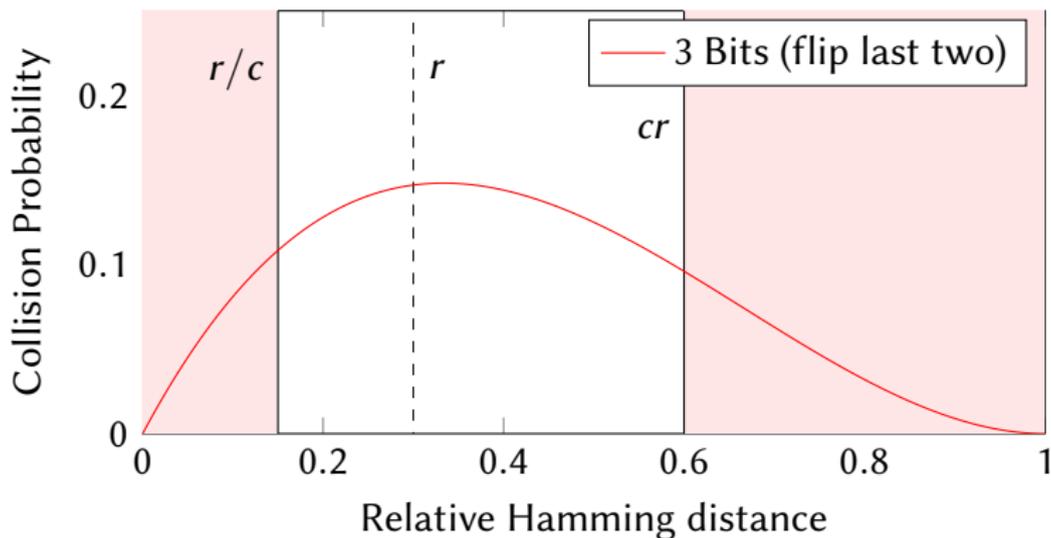
$$\mathbb{P}_{(h,g) \sim \mathcal{D}}[h(\mathbf{x}) = g(\mathbf{y})] = f(\text{dist}(\mathbf{x}, \mathbf{y})).$$

- LSH:  $f$  is monotonically decreasing
- Anti-LSH:  $f$  is monotonically increasing
- Annulus-LSH:  $f$  is unimodal and peaks in  $[r/c, cr]$ .

## Performance for Annulus Queries

- $\rho_- = \frac{\log(f(r))}{\log(f(r/c))}$
- $\rho_+ = \frac{\log(f(r))}{\log(f(cr))}$
- Space:  $O(n^{1+\rho_-+\rho_+})$
- Query time:  $O(n^{\rho_-+\rho_+})$

Bit + Anti Bitsampling collision probability



# Performance of Annulus Queries

## Bitsampling

- “optimal” as LSH for  $\{0, 1\}^d$  under Hamming distance
- $\rho_+ = O(1/c)$

## Anti Bitsampling

- $\rho_- = O(1/\log c)$
- Bad at distinguishing “close” and “very close” points.

Query time:  $n^{O(1/\log c)}$ , worse than LSH for near-neighbor queries.

Can we do better?

# Performance of Annulus Queries

## Bitsampling

- “optimal” as LSH for  $\{0, 1\}^d$  under Hamming distance
- $\rho_+ = O(1/c)$

## Anti Bitsampling

- $\rho_- = O(1/\log c)$
- Bad at distinguishing “close” and “very close” points.

Query time:  $n^{O(1/\log c)}$ , worse than LSH for near-neighbor queries.

Can we do better?

$$0011010 \mapsto \frac{1}{\sqrt{d}}(-1, -1, +1, +1, -1, +1, -1)$$

## Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

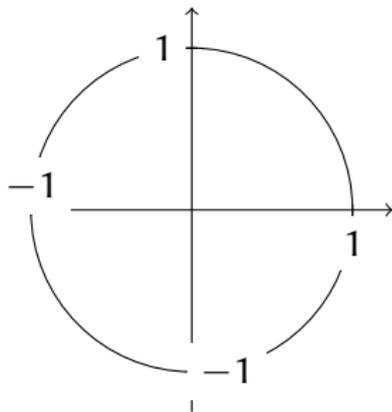
Store  $\mathcal{U}_{\mathbf{a}, t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{\mathbf{a},t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

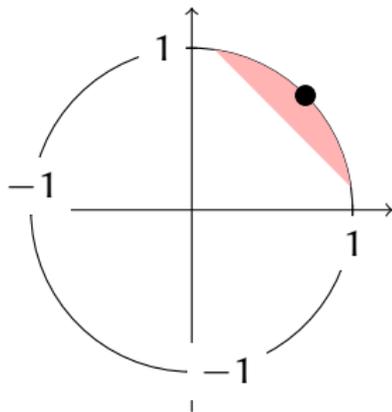


# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{\mathbf{a}, t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$



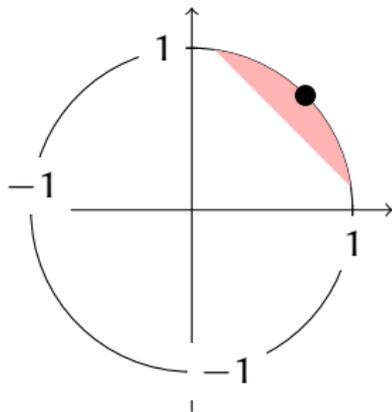
# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{\mathbf{a},t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{\mathbf{a},t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \geq t$



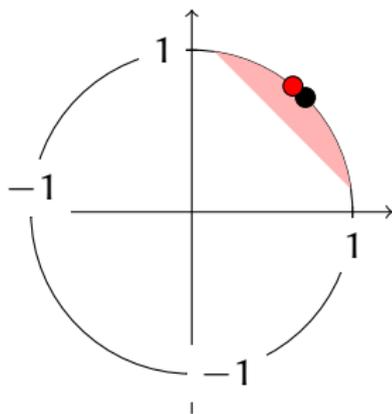
# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{\mathbf{a},t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{\mathbf{a},t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \geq t$



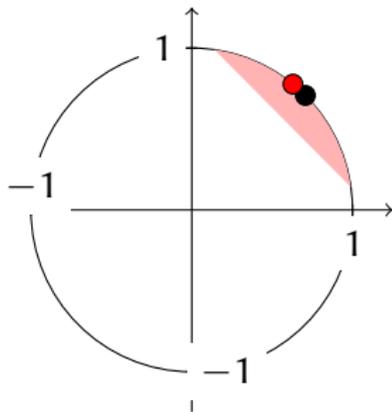
# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{\mathbf{a},t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{\mathbf{a},t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \leq -t$

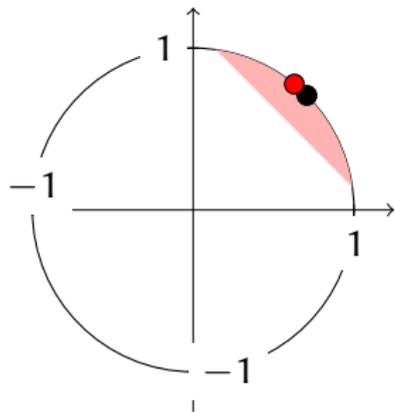


## Filter construction (Unit sphere)

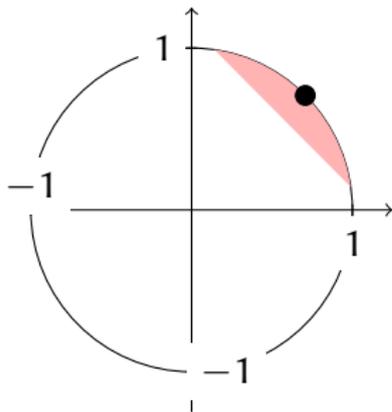
(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{a,t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$



Inspect  $\mathcal{U}_{a,t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \leq -t$



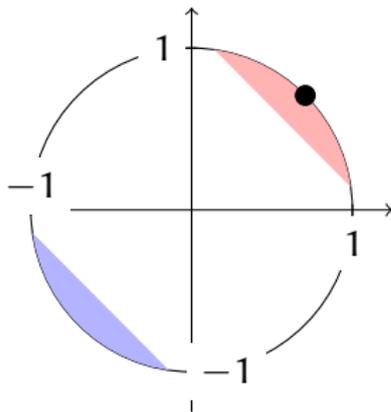
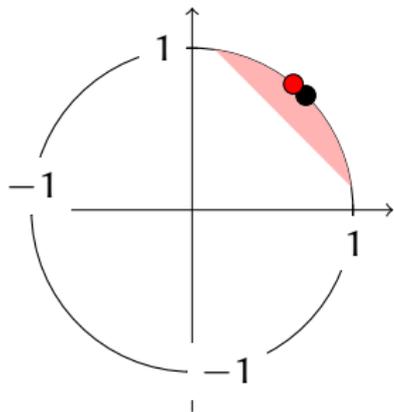
## Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{a,t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{a,t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \leq -t$



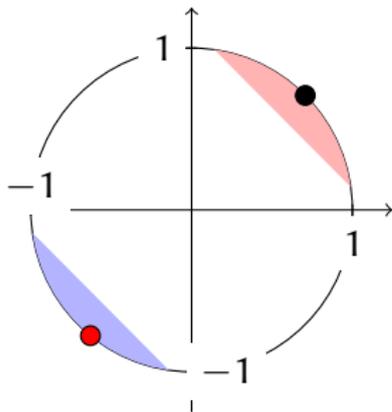
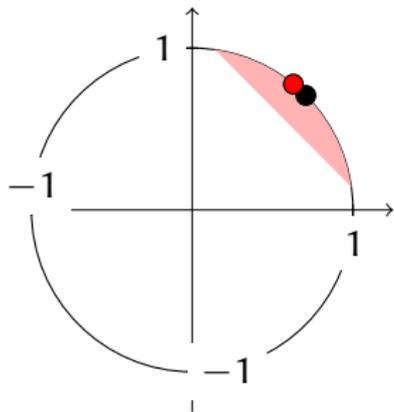
## Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{a,t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{a,t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \leq -t$



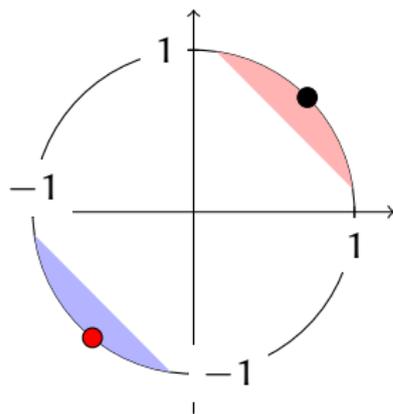
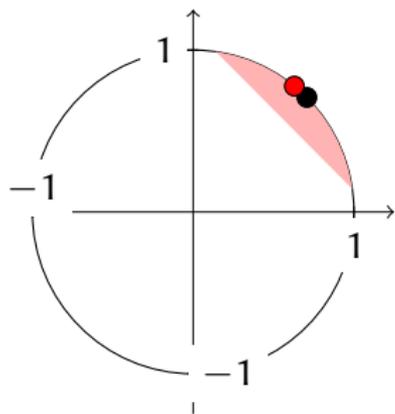
# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{a,t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{a,t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \leq -t$



**LSF:**

- $\rho_+ = O(1/c^2)$
- optimal

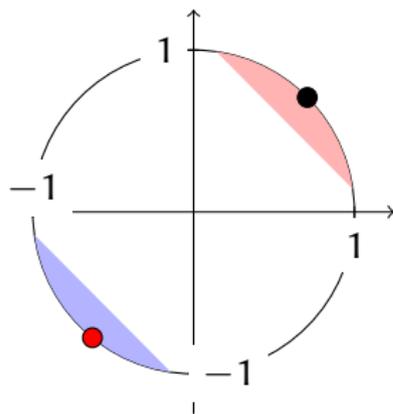
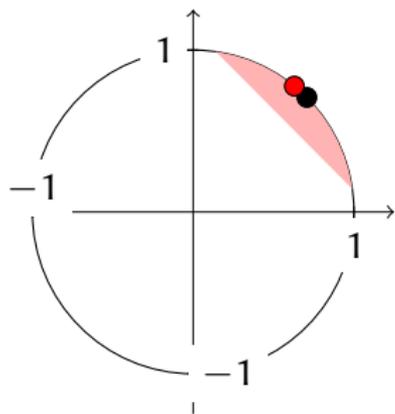
# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{a,t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{a,t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \leq -t$



**LSF:**

- $\rho_+ = O(1/c^2)$
- optimal

**Anti-LSF:**

- $\rho_- = O(1/c^2)$
- optimal?

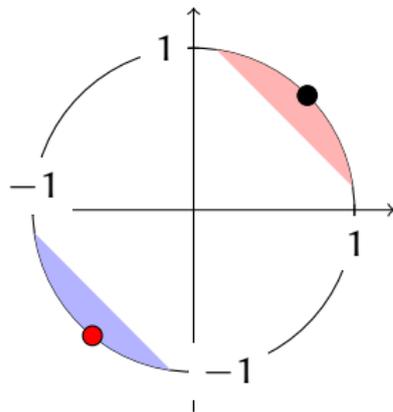
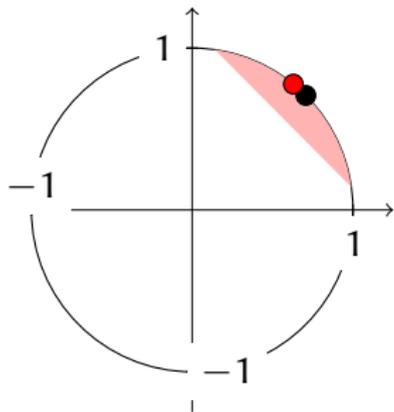
# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{a,t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{a,t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \leq -t$



**LSF:**

- $\rho_+ = O(1/c^2)$
- optimal

**Annulus-LSF:**

- $\rho_+ + \rho_- = O(1/c^2)$
- optimal?

**Anti-LSF:**

- $\rho_- = O(1/c^2)$
- optimal?

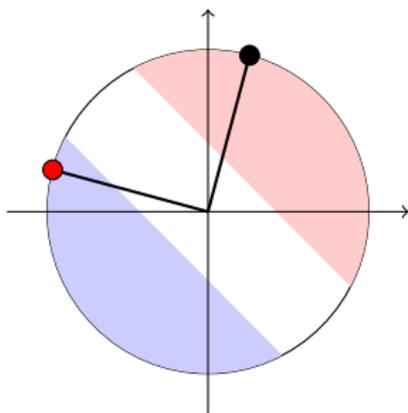
# Filter construction (Unit sphere)

(Becker et al. 2016, Christiani 2017, Andoni et al. 2017)

Fix  $t > 0$ . Sample  $\mathbf{a} \sim \mathcal{N}^d(0, 1)$ , and

Store  $\mathcal{U}_{a,t} = \{\mathbf{x} \in S \mid \langle \mathbf{a}, \mathbf{x} \rangle \geq t\}$

Inspect  $\mathcal{U}_{a,t}$  if  $\langle \mathbf{a}, \mathbf{y} \rangle \leq -t$



## LSF:

- $\rho_+ = O(1/c^2)$
- optimal

## Annulus-LSF:

- $\rho_+ + \rho_- = O(1/c^2)$
- optimal?

## Anti-LSF:

- $\rho_- = O(1/c^2)$
- optimal?

# A Lower Bound on the Unit Sphere

- Setting: distance  $\sqrt{2}$  vs. distance  $\sqrt{2}/c$  (random vs. correlated).

## Theorem

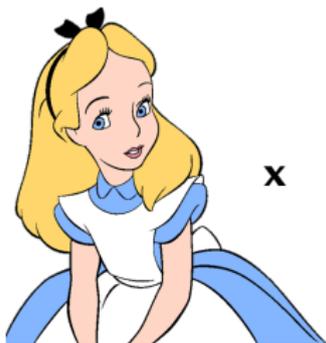
*For every distance-sensitive family with CPF  $f$  we have*

$$\rho_- = \frac{\log(f(\sqrt{2}))}{\log(f(\sqrt{2}/c))} \geq \frac{1}{2c^2 - 1}.$$

(Matches LSH lower bounds, but is **dual** to them.)

# Privacy-preserving distance estimation

Problem inspired by (Riazi et al. '16)



Alice

$$\mathbf{x} \rightarrow \text{dist}(\mathbf{x}, \mathbf{y}) \leq r? \leftarrow \mathbf{y}$$



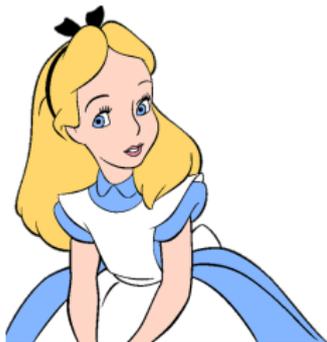
Bob

**Goals:** Don't reveal vectors, don't reveal actual distance.

For an approximation factor  $c > 1$ , and parameters  $\varepsilon, \delta > 0$ :

- $\text{dist}(\mathbf{x}, \mathbf{y}) \leq r$ , we say “Yes” with probability at least  $1 - \varepsilon$ .
- $\text{dist}(\mathbf{x}, \mathbf{y}) \geq cr$ , we say “No” with probability at least  $1 - \delta$ .

## Solution via “step-function CPFs”



**x**

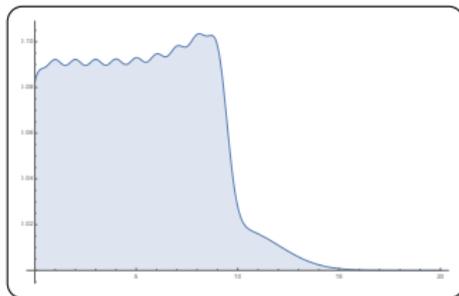


**y**

## Solution via “step-function CPFs”



**x**

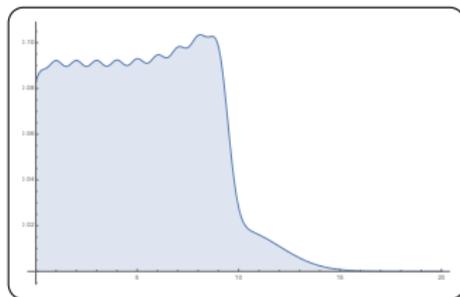


**y**

## Solution via “step-function CPFs”



**x**

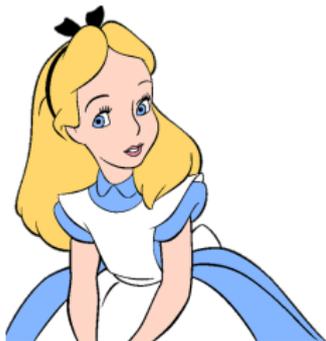


Choose  $(h_1, g_1), \dots, (h_t, g_t) \sim \mathcal{D}$

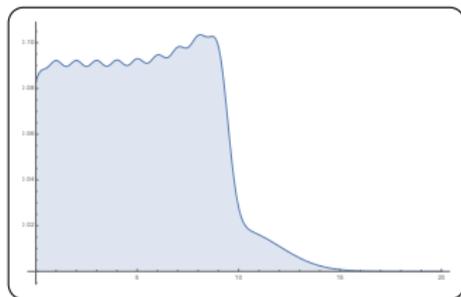


**y**

## Solution via “step-function CPFs”



**x**



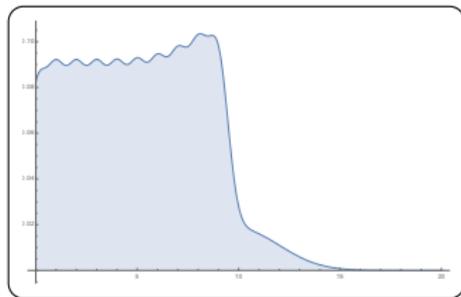
Choose  $(h_1, g_1), \dots, (h_t, g_t) \sim \mathcal{D}$



**y**



# Solution via “step-function CPFs”



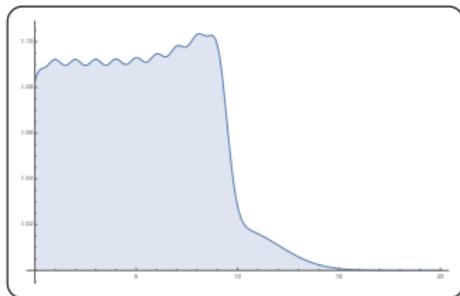
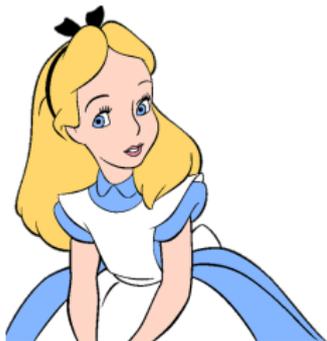
**x**

Choose  $(h_1, g_1), \dots, (h_t, g_t) \sim \mathcal{D}$

**y**



# Solution via “step-function CPFs”



$\mathbf{x}$

Choose  $(h_1, g_1), \dots, (h_t, g_t) \sim \mathcal{D}$

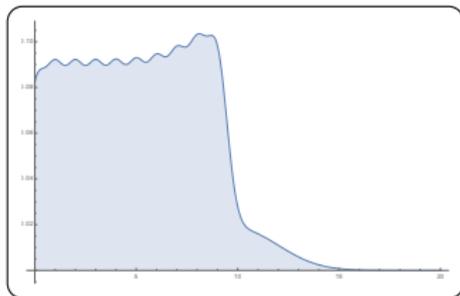
$\mathbf{y}$



$$A = \{h_1(\mathbf{x}), \dots, h_t(\mathbf{x})\}$$

$$B = \{g_1(\mathbf{y}), \dots, g_t(\mathbf{y})\}$$

# Solution via “step-function CPFs”



$\mathbf{x}$

Choose  $(h_1, g_1), \dots, (h_t, g_t) \sim \mathcal{D}$

$\mathbf{y}$

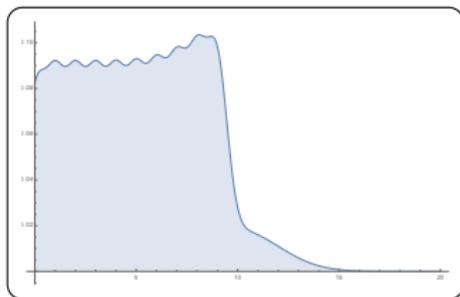


$$A = \{h_1(\mathbf{x}), \dots, h_t(\mathbf{x})\}$$

$$B = \{g_1(\mathbf{y}), \dots, g_t(\mathbf{y})\}$$



# Solution via “step-function CPFs”



$\mathbf{x}$

Choose  $(h_1, g_1), \dots, (h_t, g_t) \sim \mathcal{D}$

$\mathbf{y}$



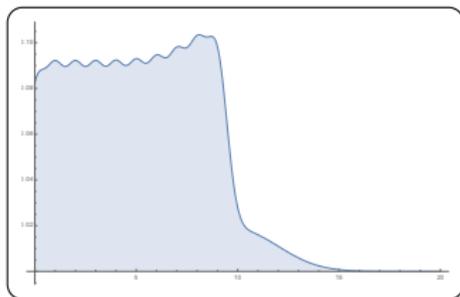
$$A = \{h_1(\mathbf{x}), \dots, h_t(\mathbf{x})\}$$

$$B = \{g_1(\mathbf{y}), \dots, g_t(\mathbf{y})\}$$



“Yes”  $\Leftrightarrow A \cap B \neq \emptyset$

# Solution via “step-function CPFs”



$\mathbf{x}$

Choose  $(h_1, g_1), \dots, (h_t, g_t) \sim \mathcal{D}$

$\mathbf{y}$



$$A = \{h_1(\mathbf{x}), \dots, h_t(\mathbf{x})\}$$

$$B = \{g_1(\mathbf{y}), \dots, g_t(\mathbf{y})\}$$

“Yes”  $\Leftrightarrow A \cap B \neq \emptyset$

Checked using “privacy-preserving set intersection”

## Conclusion & Open Problems

- Introduced notion of “distance-sensitive” hash families
  - ... generalization of locality-sensitive hashing
- Applications:
  - ▶ annulus queries
  - ▶ estimating a function
  - ▶ privacy-preserving distance estimation
- Provided some initial constructions and a lower bound on “anti-LSH”

## Conclusion & Open Problems

- Introduced notion of “distance-sensitive” hash families  
... generalization of locality-sensitive hashing
- Applications:
  - ▶ annulus queries
  - ▶ estimating a function
  - ▶ privacy-preserving distance estimation
- Provided some initial constructions and a lower bound on “anti-LSH”

### Open:

- Which functions  $f$  admit a distance-sensitive hash family?
- Better solution to annulus queries than combining LSH + anti-LSH (which gives  $O(n^{2\rho})$  query time)?

## Conclusion & Open Problems

- Introduced notion of “distance-sensitive” hash families  
... generalization of locality-sensitive hashing
- Applications:
  - ▶ annulus queries
  - ▶ estimating a function
  - ▶ privacy-preserving distance estimation
- Provided some initial constructions and a lower bound on “anti-LSH”

### Open:

- Which functions  $f$  admit a distance-sensitive hash family?
- Better solution to annulus queries than combining LSH + anti-LSH (which gives  $O(n^{2\rho})$  query time)?

**Thank you!**