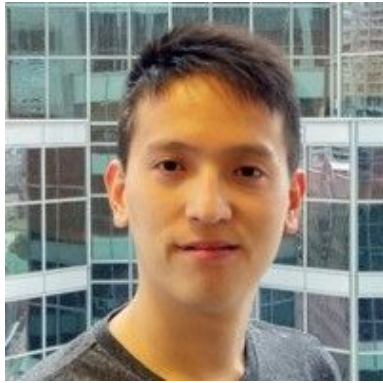
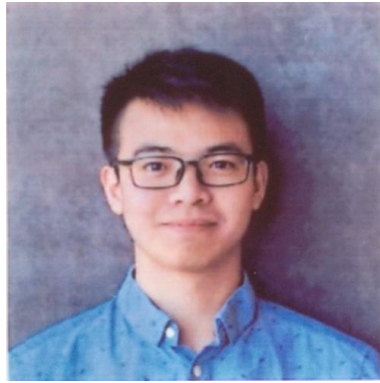


# Dynamic Measurement Scheduling for Event Forecasting Using Deep RL



Chun-Hao Chang  
(Kingsley)



Mingjie Mai



Anna Goldenberg



University of Toronto, Vector Institute  
The Hospital of Sickkids



# Motivation



# Motivation



# Outcomes

Sepsis

Mortality

Treatments

⋮

# Motivation



# Outcomes

Sepsis

Mortality

Treatments

⋮

# Measurements

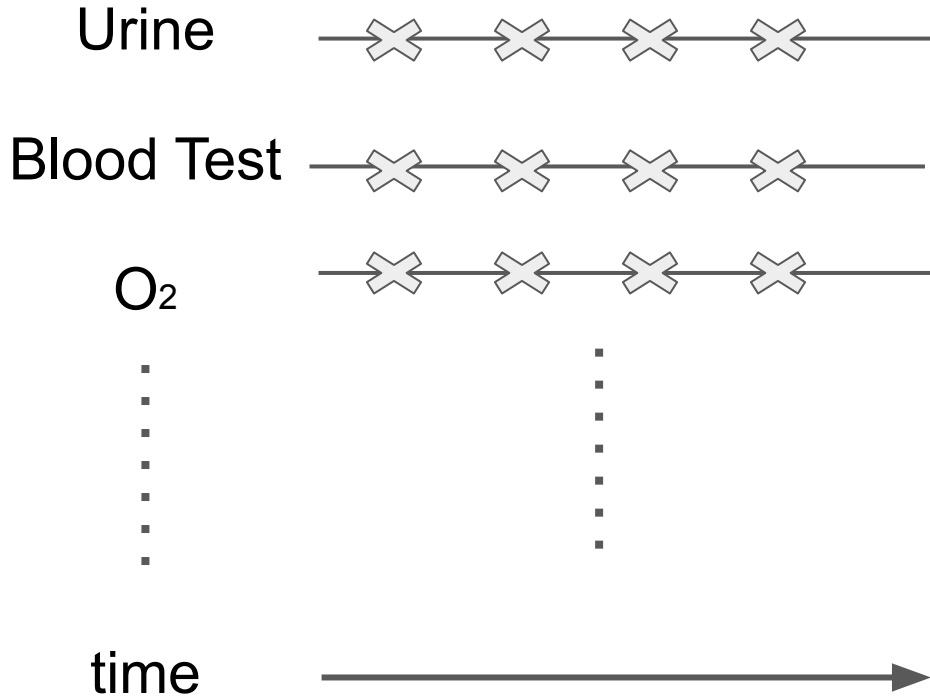
Lactate

Blood Test

O<sub>2</sub>

⋮

# Uniform policy



Waste lots of measurements

# Dynamic policy

Healthy

Critical

Urine



Blood Test



O<sub>2</sub>



⋮

⋮

time



Adaptive to patient's condition

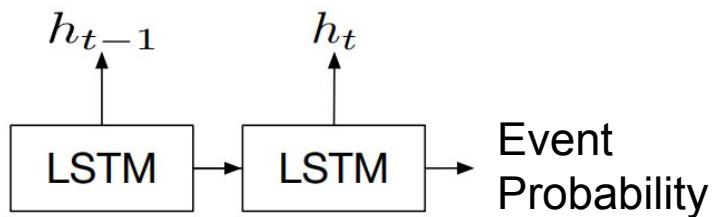
- Cost-saving
- Early detection

# Contributions

- RL framework for **cost-sensitive scheduling** of measurements in **time-series**
- **Scalable** to large number of measurements
- Promising results in a **real-world ICU dataset** (MIMIC3)

# System Pipeline

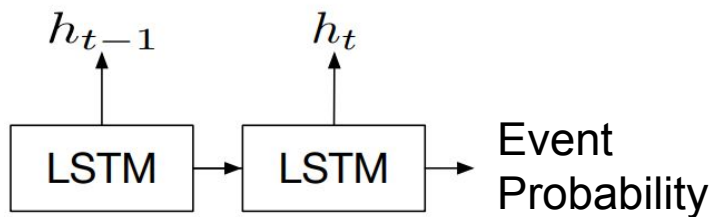
## *Forecasting Model*



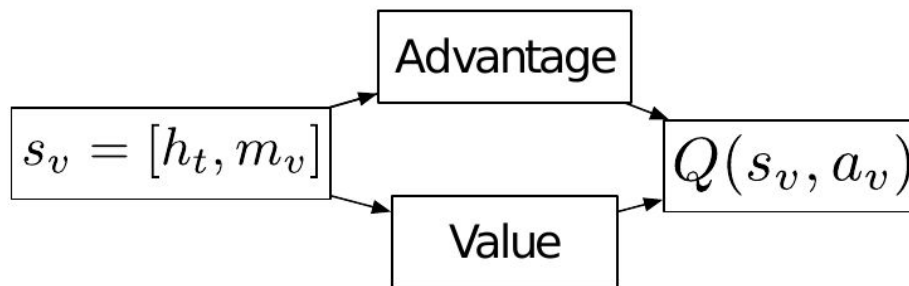


# System Pipeline

## *Forecasting Model*



## Policy Learning - Dueling Deep Q Network



# Problem of large action space

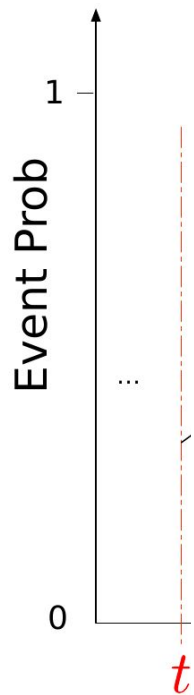
- Any combination of  $D$  measurements is a valid action
  - $2^D$  possible actions

# Problem of large action space

- Any combination of  $D$  measurements is a valid action
  - $2^D$  possible actions
  
- Solutions:
  - Independent Policy
  - **Sequential Policy**
    - Only  $D+1$  actions

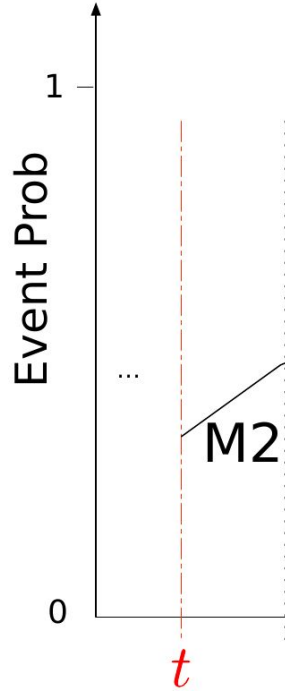
# Policy Illustration

M: Measurement     $A = \{M1, M2, M3, \Omega? \}$      $\Omega$ : Stop-Action



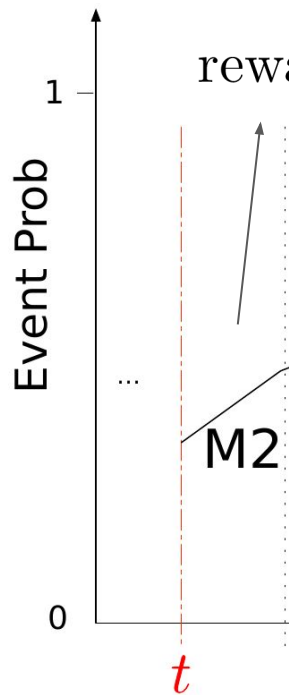
# Policy Illustration

M: Measurement  $A = \{M1, M2, M3, \Omega\}$   $\Omega$ : Stop-Action



# Policy Illustration

M: Measurement    A = {M1, M2, M3,  $\Omega?$  }     $\Omega$ : Stop-Action



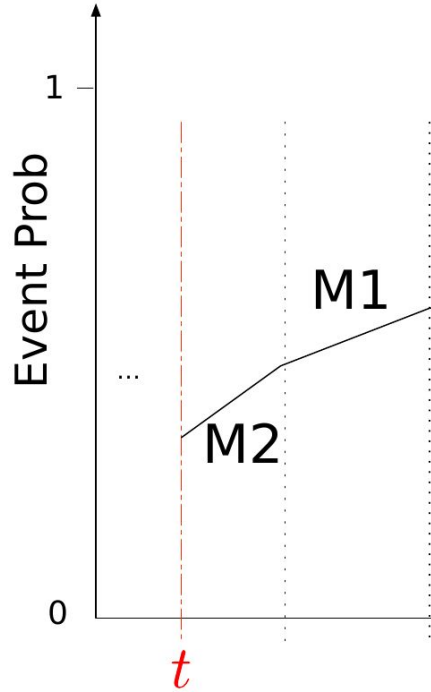
$$\text{reward } r = \Delta_P(M2) - \lambda \times c(M2)$$

Prob Gain from M2

Measurement cost

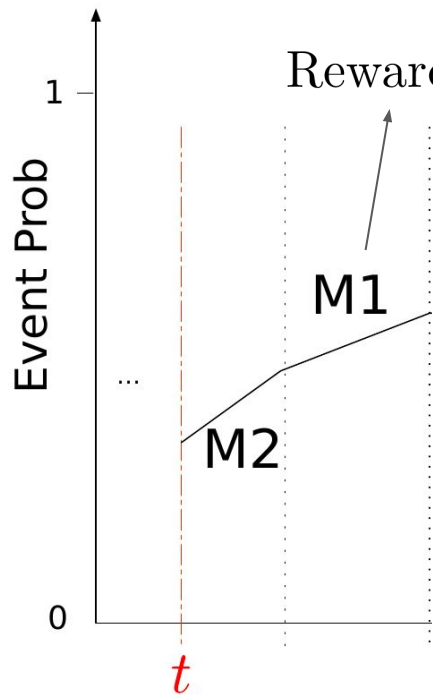
# Policy Illustration

M: Measurement  $A = \{M1, M2, M3, \Omega?\}$   $\Omega$ : Stop-Action



# Policy Illustration

M: Measurement  $A = \{M1, M2, M3, \Omega\}$   $\Omega$ : Stop-Action



$$\text{Reward } r = \Delta_P(M1) - \lambda \times c(M1)$$

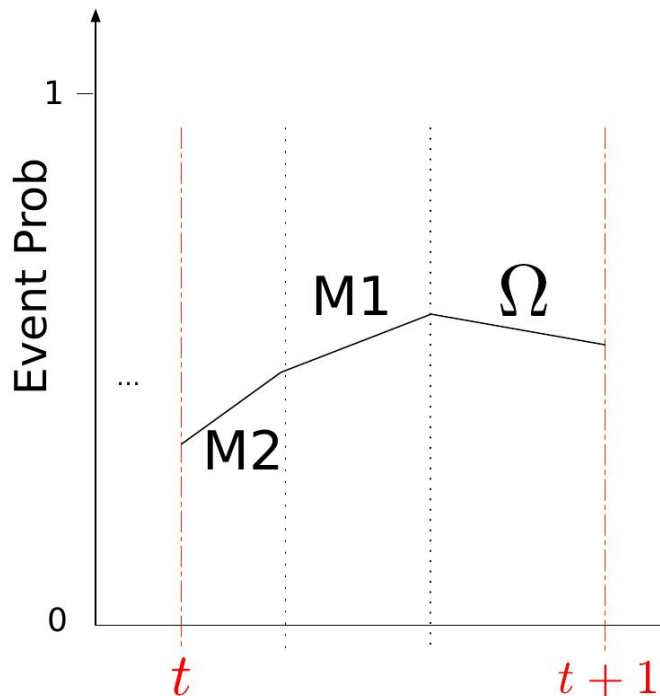
Prob Gain from M1

Measurement cost



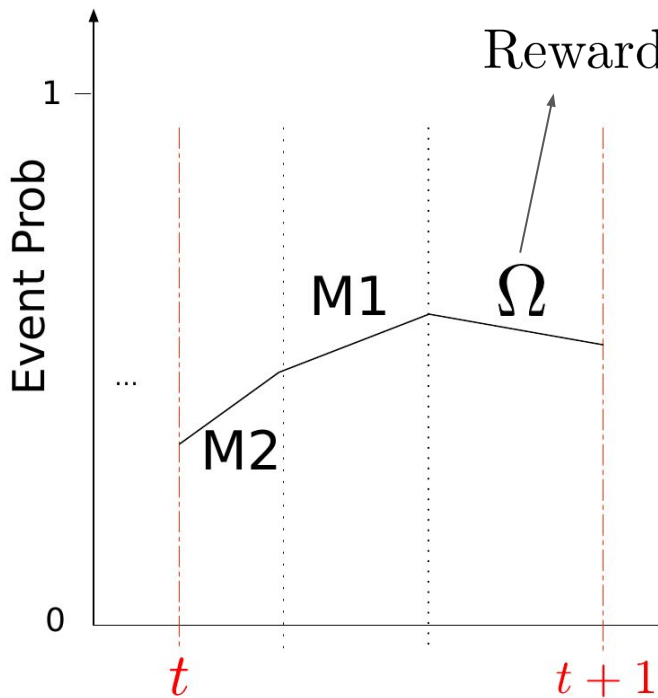
# Policy Illustration

M: Measurement  $A = \{M1, M2, M3, \Omega?\}$   $\Omega$ : Stop-Action



# Policy Illustration

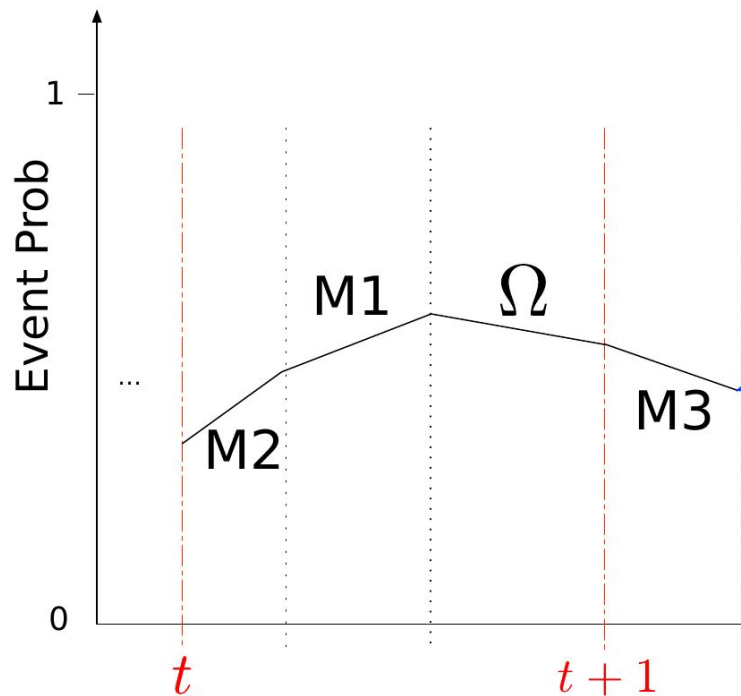
M: Measurement     $A = \{M1, M2, M3, \Omega\}$      $\Omega$ : Stop-Action



No Measurement Cost

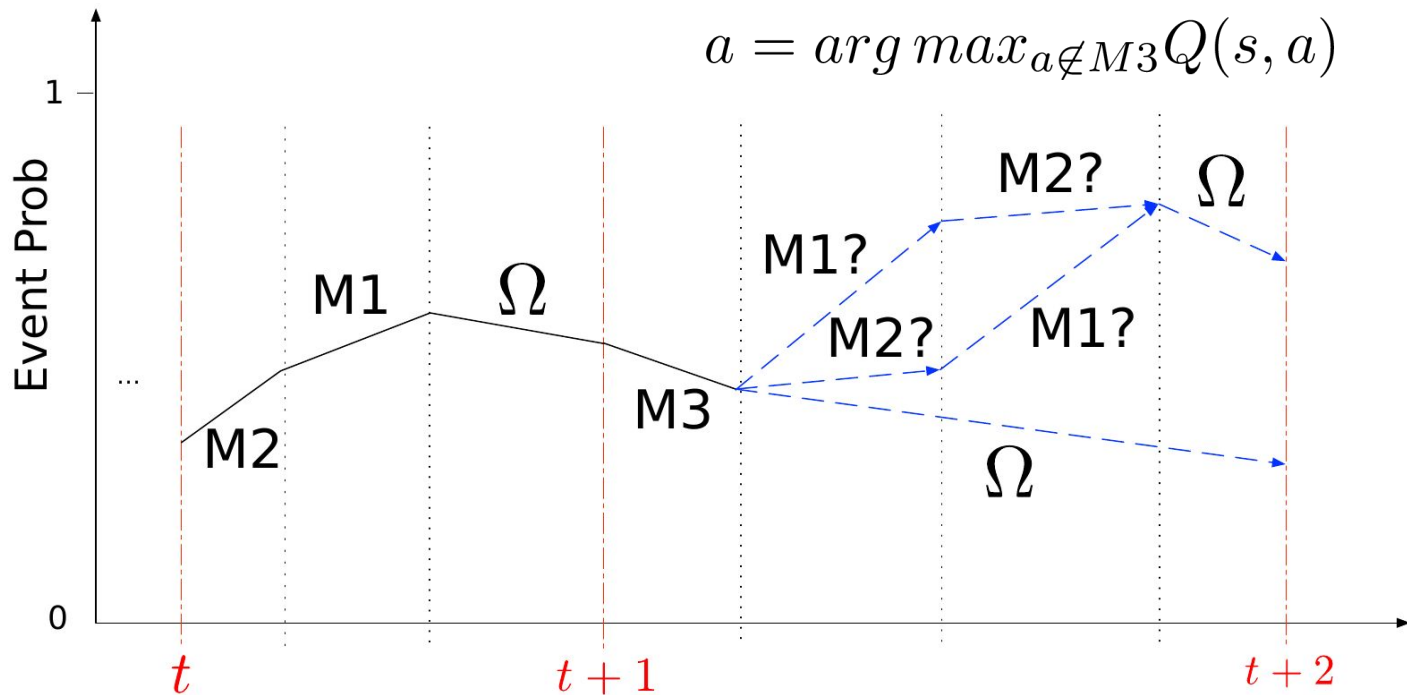
# Policy Illustration

M: Measurement     $A = \{M1, M2, M3, \Omega\}$      $\Omega$ : Stop-Action

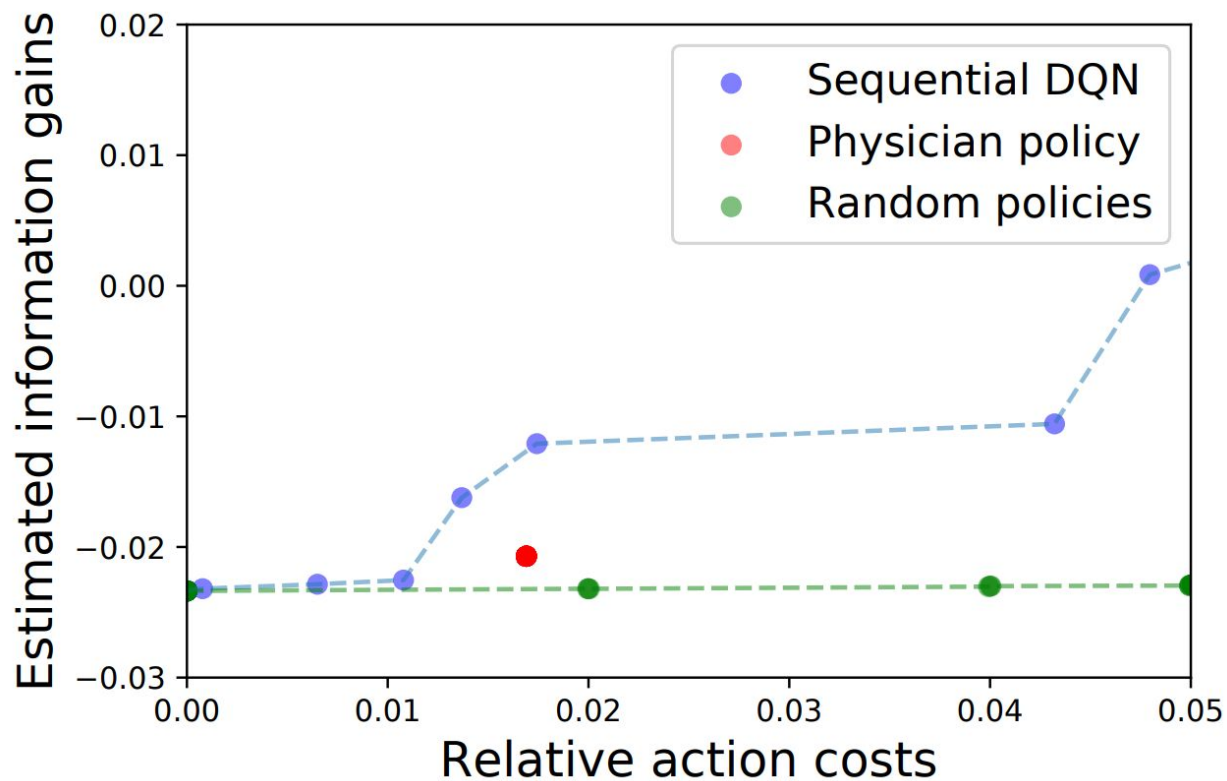


# Policy Illustration

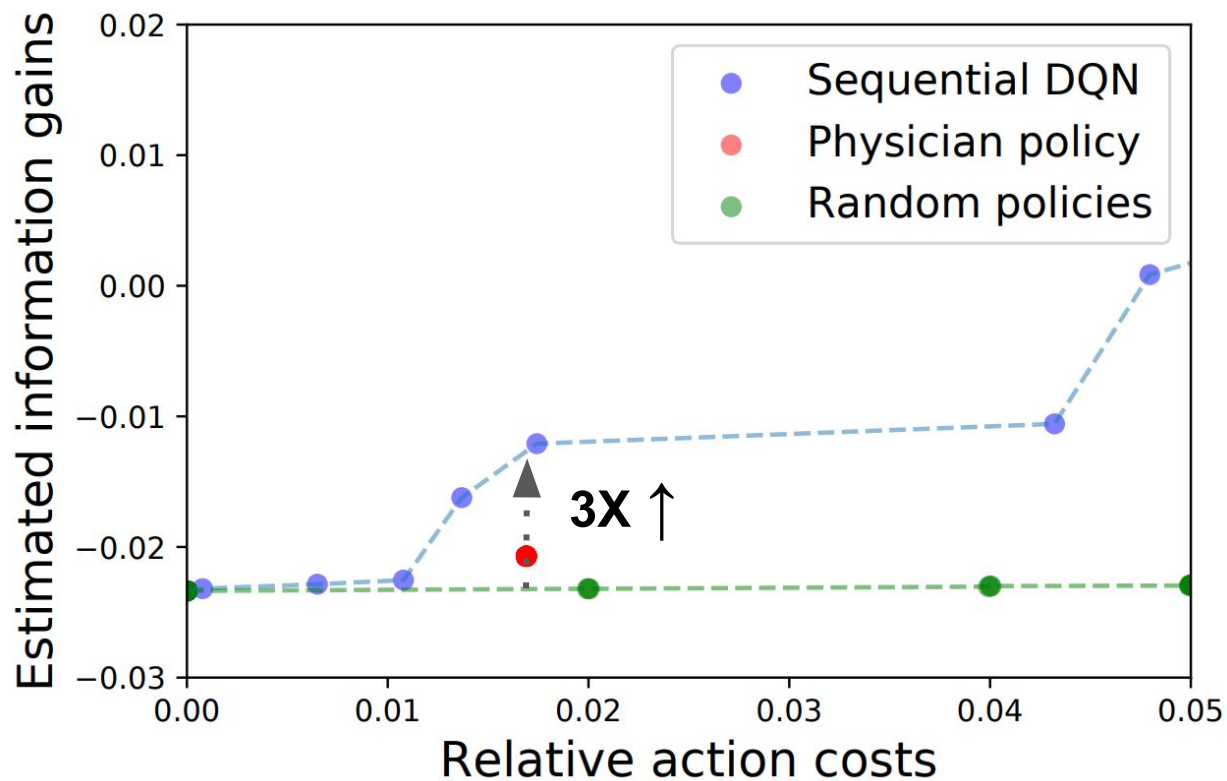
M: Measurement  $A = \{M1, M2, M3, \Omega?\}$   $\Omega$ : Stop-Action



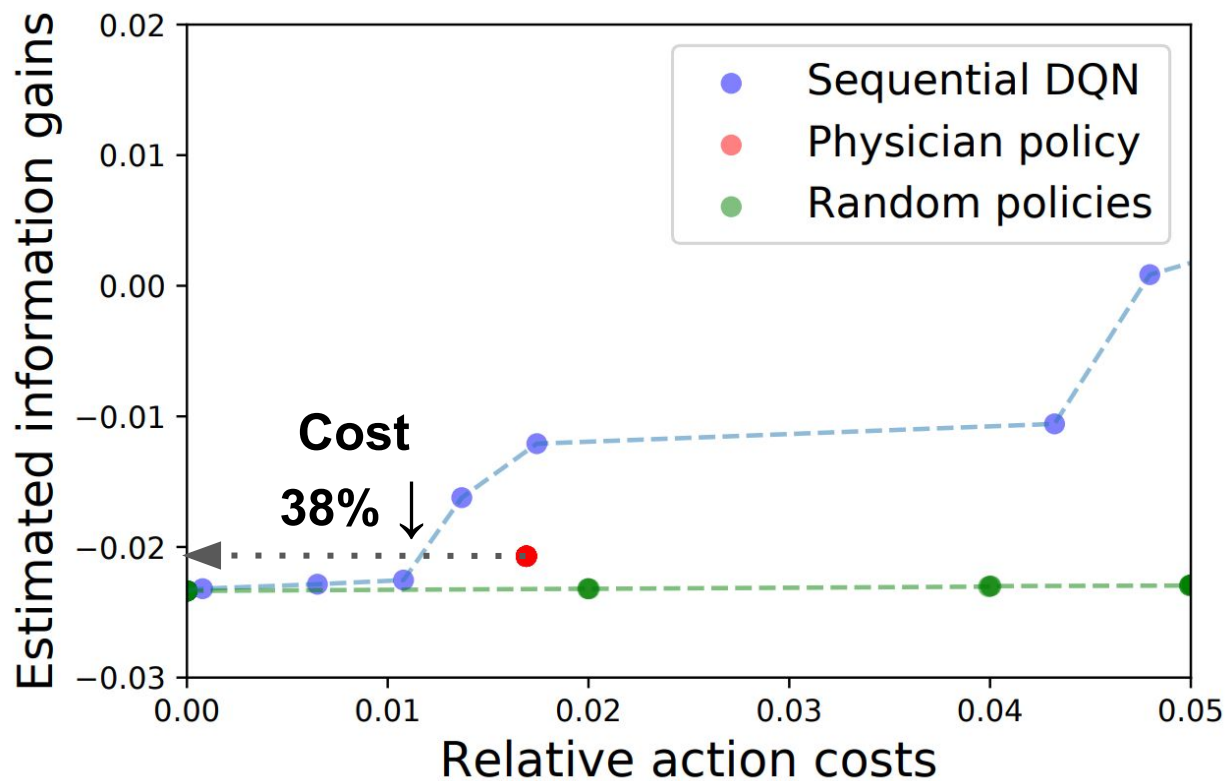
# Off-Policy Policy Evaluation



# Off-Policy Policy Evaluation

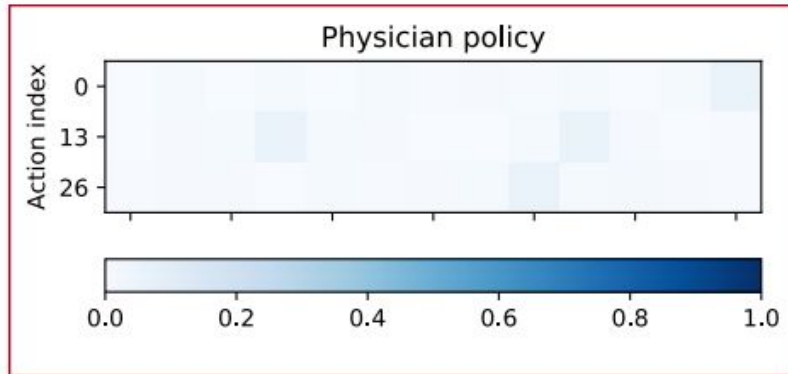


# Off-Policy Policy Evaluation



# Measurements frequency

## Physician's policy

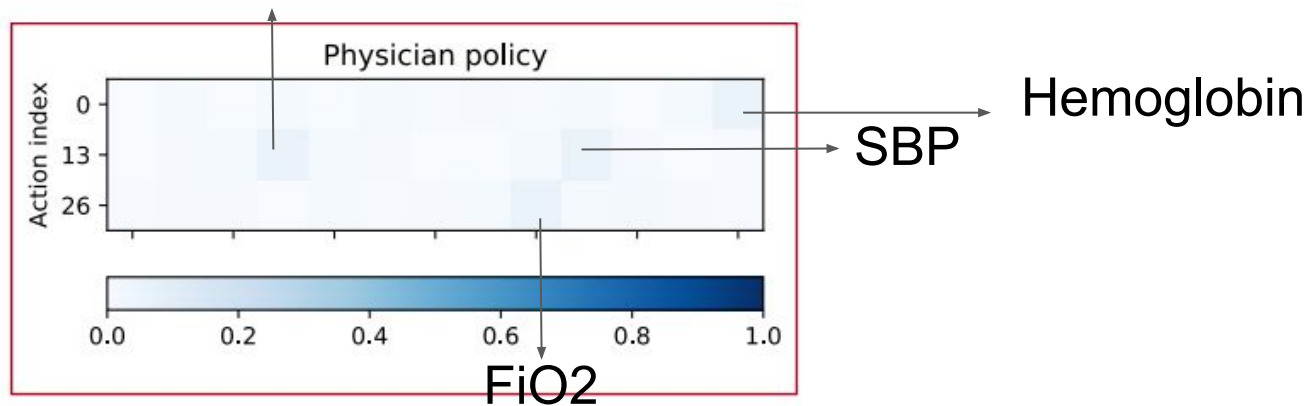




# Measurements frequency

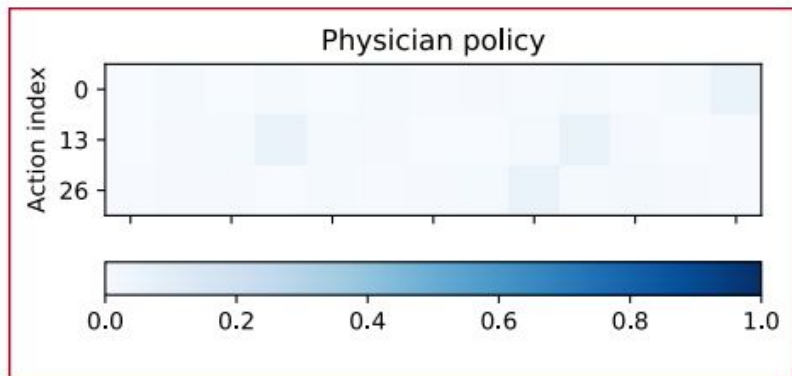
## Physician's policy

Phosphate

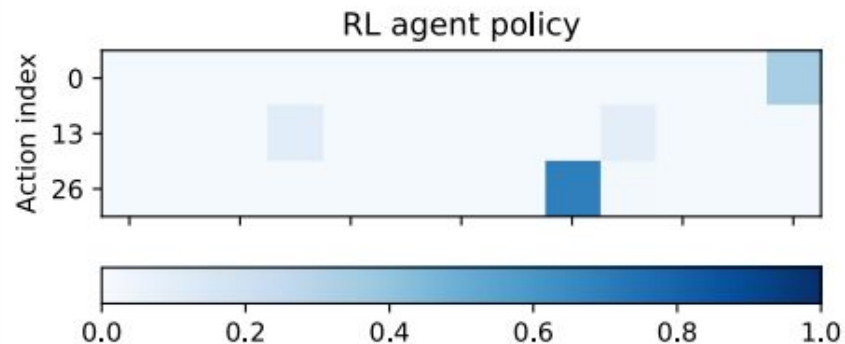


# Measurements frequency

## Physician's policy



## RL policy



# Dynamic Measurement Scheduling for Event Forecasting Using Deep RL

- Code and data preprocessing are released at <https://github.com/zzzace2000/autodiagnosis>

- Poster **# 247** @ Pacific Ballroom
- Wed 06:30 -- 09:00 PM



