

# Disentangled Representation Learning for Controllable Image Synthesis: an Information-Theoretic Perspective

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## Introduction

It is desirable to make the latent variables in a generative model disentangled and interpretable. However, the learned representation in a Variational AutoEncoder (VAE) or a Generative Adversarial Network (GAN) is usually entangled and not interpretable. Therefore, we propose to use the framework in Fig. 1 for learning disentangled representation and performing controllable image synthesis. The proposed framework is a variant of VAE that has its latent code partitioned:  $z_2$  is the representation of the specified feature  $f(x)$  while  $z_1$  is complementary to  $z_2$ .  $z_1$  is encoded from the input image and  $z_2$  is encoded from its feature  $f(x)$ . If this disentangled representation can be learned, then one can control the properties of the output image by manipulating the two latent codes.

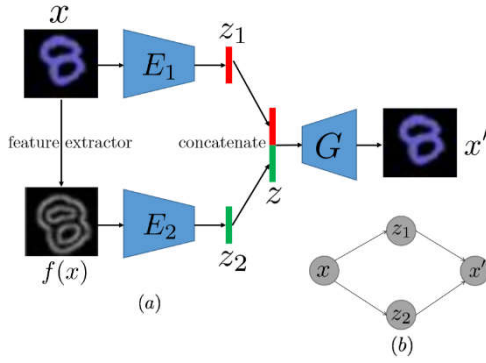
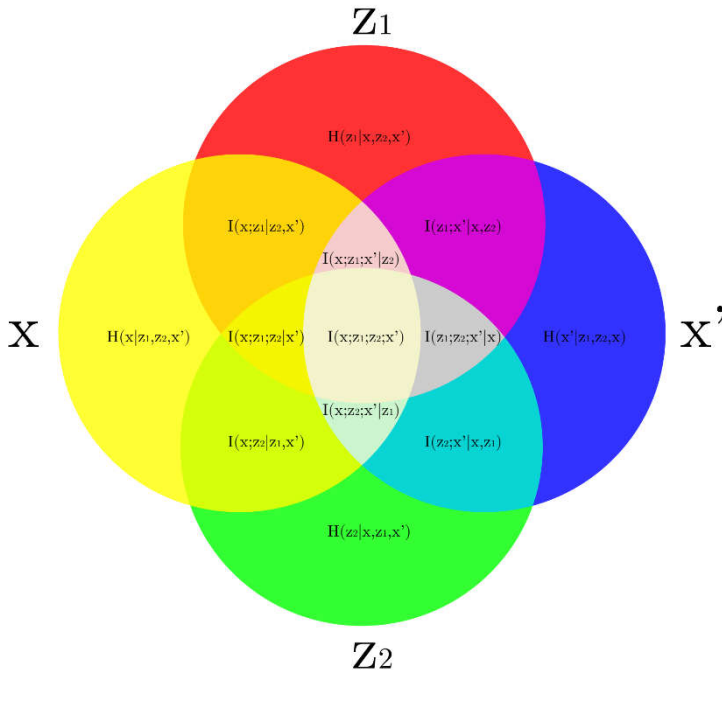


Fig. 1. model architecture and the relationship of  $x$ ,  $z_1$ ,  $z_2$  and  $x'$  described as a probabilistic directed graphical model. The CMNST dataset is taken as an example.

## Analysis

In the framework, since  $z_1$  can contain complete information about the input,  $z_2$  may be ignored in the training of VAE. We analyze the problem from the perspective of multivariate mutual information:

In order to make the Generator utilize its second input, maximizing the mutual information between  $z_2$  and the output  $x'$  might be the solution. Unfortunately, this cannot help as the mutual information between  $z_2$  and  $x'$  can be shared by  $z_1$ . Therefore, the conditional mutual information  $I(z_2; x' | z_1)$  should be maximized instead.



## Method

We derive lower bounds of the conditional mutual information when fusing two images (encode  $z_1$  from input image  $x$ , encode  $z_2$  from another independently sampled input image  $x$ , concatenate them and produce a fusion image  $x$ ) and incorporate them into the loss of the Encoders and the Generator:

$$I(\tilde{z}_2; \hat{x} | z_1) \geq \mathbb{E}[\log q(\tilde{z}_2 | z_1, \hat{x})] + H(\tilde{z}_2 | z_1)$$

$$I(\tilde{z}_2; \hat{x} | z_1) \geq \mathbb{E}[\log q^*(f(\tilde{x}) | z_1, \hat{x})] + H(f(x))$$

When the second term in the bounds are constant, under a Bernoulli or Gaussian assumption, maximizing the bounds is equivalent to minimizing the reconstruction loss of  $\tilde{z}_2$  or  $f(\tilde{x})$ :

$$L_{f1} = -\mathbb{E}[\log q(\tilde{z}_2 | z_1, \hat{x})]$$

$$L_{f2} = \mathbb{E}[\|f(G(z_1, \tilde{z}_2)) - f(\tilde{x})\|_2^2]$$

For discrete features, we try to minimize  $L_{f1}$ ; for continuous features, we try to minimize  $L_{f2}$ .

We also train a cGAN for better visual quality:

$$L_D = -\mathbb{E}[\log D(z_2, x') + \log(1 - D(\tilde{z}_2, \hat{x}))] \quad L_{GAN} = -\mathbb{E}[\log(D(\tilde{z}_2, \hat{x}))]$$

The overall loss for the Encoders and the Generator is

$$L = L_{VAE} + \lambda_3 L_f + \lambda_4 L_{GAN}$$

## Results

