

Nonlinear and non-Gaussian state-space modelling by means of hidden Markov models

Roland Langrock
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St Andrews, 13 December 2010

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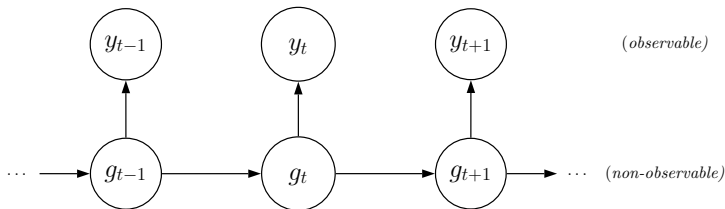
1 State-space models

- Basics
- Approximation via hidden Markov models

2 Application

- Glacial varve thickness

(General) state-space model (SSM):

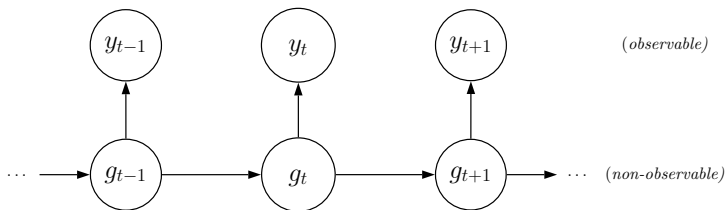


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$$g_t = b(g_{t-1}, \eta_t)$$

- a , b : known functions (not necessarily linear)
- ϵ_t , η_t iid (not necessarily $\sim \mathcal{N}$)

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Example 1. Stochastic volatility model:

$$y_t = \epsilon_t \beta \exp(g_t/2)$$

$$g_t = \phi g_{t-1} + \sigma \eta_t$$

- $\epsilon_t \stackrel{iid}{\sim} t_\nu$ or $\mathcal{N}(0, 1)$, $\eta_t \stackrel{iid}{\sim} \mathcal{N}(0, 1)$
- g_t determines variance (volatility) of y_t

Example 2. Poisson autoregression:

$$y_t \sim \text{Poisson}(\beta \exp(g_t))$$

$$g_t = \phi g_{t-1} + \sigma \eta_t$$

- $\eta_t \stackrel{iid}{\sim} \mathcal{N}(0, 1)$
- g_t determines mean (and variance) of y_t

Desired:

- parameter estimation
- state decoding
- forecasts
- model checking

SSM likelihood:

$$\mathcal{L}(\mathbf{y}) = \underbrace{\int \dots \int}_{n\text{-fold}} f(\mathbf{y}, \mathbf{g}) d\mathbf{g}$$

can not be evaluated directly...

(SSM *linear & Gaussian* → Kalman filter optimal)

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Parameter estimation in case of nonlinearity/non-Gaussianity:

- *Extended Kalman filter*
 - + simple implementation
 - in general poor approximation
- *(Generalized) method of moments*
 - + simple implementation
 - low efficiency, no state decoding
- *Monte Carlo methods*
 - + high efficiency
 - computer-intensive
 - nonstandard models require nontrivial modifications

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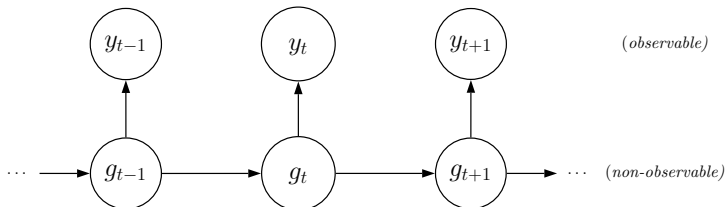
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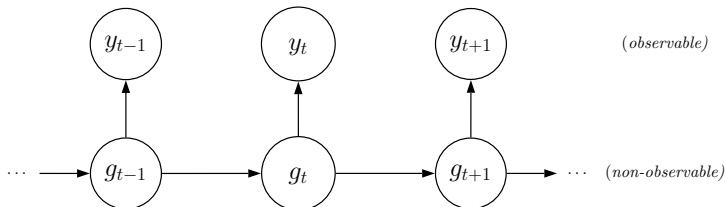
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Hidden Markov model:



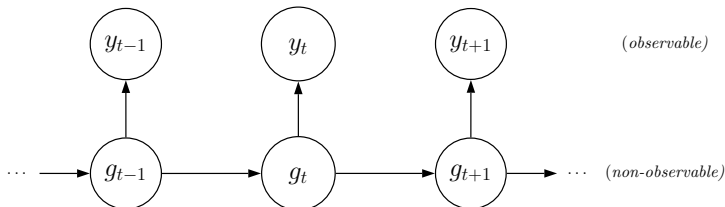
- Non-observable process: N -state Markov chain g_t
 - initial distribution $\delta_i = \mathbb{P}(g_1 = i)$
 - transition probabilities $\gamma_{ij} = \mathbb{P}(g_t = j \mid g_{t-1} = i)$
- Observable process: y_t
 - state-dependent density $f(y_t \mid g_t)$

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Key idea:

- HMMs have the same two-process structure as SSMs
- in SSMs: g_t continuous-valued
- discretizing g_t yields approximation by HMM
- benefit: HMM methodology becomes applicable

- split essential range of g_t into m equidistant intervals

$$B_i := [b_{i-1}, b_i]$$

- b_i^* : midpoint of B_i

$$\begin{aligned} &\Rightarrow \mathcal{L}(\mathbf{y}) = \int \dots \int f(\mathbf{y}, \mathbf{g}) \, d\mathbf{g} \\ &= \int f(g_1) f(y_1 | g_1) \prod_{t=2}^n \int f(g_t | g_{t-1}) f(y_t | g_t) \, dg_n \dots dg_1 \\ &\approx \sum_{i_1=1}^m \mathbb{P}(g_1 \in B_{i_1}) f(y_1 | g_1 = b_{i_1}^*) \prod_{t=2}^n \sum_{i_t=1}^m \mathbb{P}(g_t \in B_{i_t} | g_{t-1} = b_{i_{t-1}}^*) f(y_t | g_t = b_{i_t}^*) \\ &=: \mathcal{L}_{\text{approx}}(\mathbf{y}) \end{aligned}$$

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Consider HMM with

- m -state MC (possible outcomes: midpoints b_i^*)
 - transition probabilities: $\gamma_{ij} := \mathbb{P}(g_t \in B_j | g_{t-1} = b_i^*)$
 - transition probability matrix: $\mathbf{\Gamma} = (\gamma_{ij})$
 - initial distribution: $\delta_i := \mathbb{P}(g_1 \in B_i)$
- observable process:
 - state-dependent density: $f(y_t | g_t = b_i^*)$
 - $\mathbf{P}(y_t)$: diag. matrix with i th entry $f(y_t | g_t = b_i^*)$

$$\Rightarrow \mathcal{L}_{\text{approx}}(\mathbf{y}) = \delta \mathbf{P}(y_1) \mathbf{\Gamma} \mathbf{P}(y_2) \mathbf{\Gamma} \cdots \mathbf{\Gamma} \mathbf{P}(y_{n-1}) \mathbf{\Gamma} \mathbf{P}(y_n) \mathbf{1}^t$$

→ the HMM $(\delta, \mathbf{\Gamma}, f(y_t | \cdot))$ approximates the SSM

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Pros and Cons (HMM method):

- + likelihood directly available
extensions straightforward
simple formulae for residuals, forecasts, decoding
- m and range of g_t have to be chosen
only feasible for one-dimensional state spaces

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Applications considered in Langrock (2010):

- stochastic volatility
- earthquake counts
- polio counts (seasonal)
- daily rainfall occurrence (seasonal)
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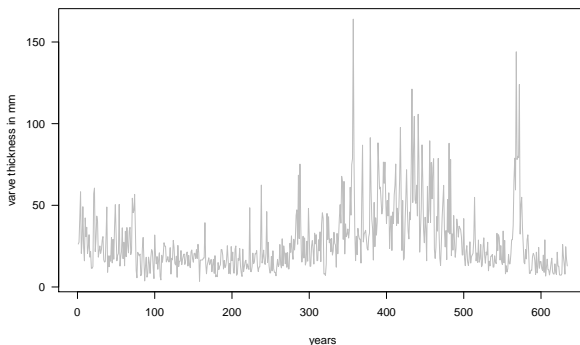


Figure: Series of glacial varve thicknesses for a location in Massachusetts.

$$y_t = \epsilon_t \beta \exp(g_t)$$
$$g_t = \phi g_{t-1} + \sigma \eta_t$$

$$\epsilon_t \sim \text{Gamma}(\text{shape} = c_v^{-2}, \text{scale} = c_v^2)$$

Properties:

- $\mathbb{E}(y_t | g_t) = \beta \exp(g_t)$
- (Conditional) coefficient of variation:

$$\frac{\text{sd}(y_t | g_t)}{\mathbb{E}(y_t | g_t)} = c_v$$

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Table: *Estimated model parameters and bootstrap 95% confidence intervals (400 replications).*

para.	estimate	c.i.
ϕ	0.95	[0.90, 0.97]
σ	0.15	[0.11, 0.19]
β	24.42	[19.1, 31.1]
c_v	0.40	[0.37, 0.42]

resolution: $m = 200$

g_t – range: $b_0 = -3, b_m = 3$

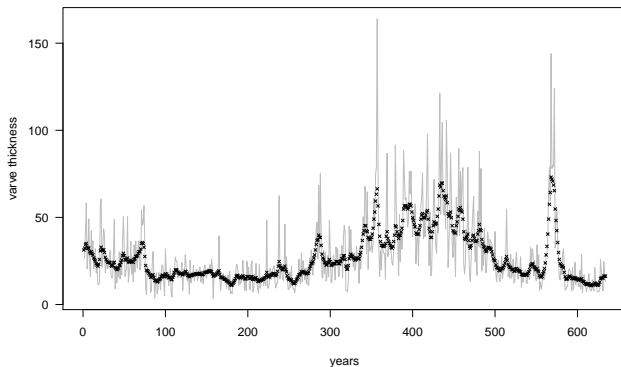


Figure: Series of glacial varve thicknesses (solid grey line) and decoded mean sequence of the fitted gamma SSM (crosses).

Summary

- HMM approximation convenient in SSM context
- whole HMM methodology applicable
- simple implementation of standard and nonstandard models



Langrock, R., MacDonald, I. M., Zucchini, W., 2010

Estimating standard and nonstandard stochastic volatility models using structured hidden Markov models. (*submitted*)



Langrock, R., 2010

Some applications of nonlinear and non-Gaussian state-space modeling by means of hidden Markov models. (*submitted*)