Package ‘RcppSMC’

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Description R access to the Sequential Monte Carlo Template Classes by Johansen <doi:10.18637/jss.v030.i06> is provided. At present, four additional examples have been added, and the first example from the JSS paper has been extended. Further integration and extensions are planned.
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blockpfGaussianOpt  
Block Sampling Particle Filter (Linear Gaussian Model; Optimal Proposal)  

Description
The blockpfGaussianOpt function provides a simple example for RcppSMC. It is based on a block sampling particle filter for a linear Gaussian model. This is intended only to illustrate the potential of block sampling; one would not ordinarily use a particle filter for a model in which analytic solutions are available. The 'optimal' block sampler in the sense of Doucet, Briers and Senecal (2006) can be implemented in this case.

The simGaussian function simulates data from the associated linear Gaussian state space model.

Usage

blockpfGaussianOpt(data, particles=1000, lag=5, plot=FALSE)
simGaussian(len)

Arguments

data  A vector variable containing the sequence of observations.
particles  An integer specifying the number of particles.
lag  An integer specifying the length of block to use.
plot  A boolean variable describing whether plot should illustrate the estimated path along with the uncertainty.
len  The length of the data sequence to simulate.

Details
The blockpfGaussianOpt function provides a simple example for RcppSMC. It is based on a simple linear Gaussian state space model in which the state evolution and observation equations are: x(n) = x(n-1) + e(n) and y(n) = x(n) + f(n) where e(n) and f(n) are mutually-independent standard normal random variables. The 'optimal' block-sampling proposal described by Doucet et al (2006) is employed.

The simGaussian function simulates from the same model returning both the state and observation vectors.

Value
The blockpfGaussianOpt function returns a matrix containing the final sample paths and a vector containing their weights. The logarithm of the estimated ratio of normalising constants between the final and initial distributions is also returned.

The simGaussian function returns a list containing the state and data sequences.
**Author(s)**
Adam M. Johansen and Dirk Eddelbuettel

**References**

**Examples**
```r
sim <- simGaussian(len=250)
res <- blockpfGaussianOpt(sim$data,lag=5,plot=TRUE)
```

---

**Description**
A simple example based on estimating the parameters of a linear regression model using
* Data annealing sequential Monte Carlo (LinReg).
* Likelihood annealing sequential Monte Carlo (LinRegLA).
* Likelihood annealing sequential Monte Carlo with the temperature schedule, number of MCMC repeats and random walk covariance matrices adapted online (LinRegLA_adapt).

**Usage**
```r
LinReg(model, particles = 1000, plot = FALSE)
LinRegLA(model, particles = 1000, temperatures = seq(0, 1, 0.05)^5)
LinRegLA_adapt(model, particles = 1000, resampTol = 0.5, tempTol = 0.9)
```

**Arguments**
- `model` Choice of regression model (1 for density as the predictor and 2 for adjusted density as the predictor).
- `particles` An integer specifying the number of particles.
- `plot` A boolean variable to determine whether to plot the posterior estimates.
- `temperatures` In likelihood annealing SMC the targets are defined as $P(y|\theta)^\gamma P(\theta)$ where $0 = \gamma_0 \leq \ldots \leq \gamma_T = 1$ can be referred to as the temperatures, $P(y|\theta)$ is the likelihood and $P(\theta)$ is the prior.
- `resampTol` The adaptive implementation of likelihood annealing SMC allows for the resampling tolerance to be specified. This parameter can be set to a value in the range [0,1) corresponding to a fraction of the size of the particle set or it may be set to an integer corresponding to an actual effective sample size.
- `tempTol` A tolerance for adaptive choice of the temperature schedule such that the conditional ESS is maintained at tempTol*particles.
Details

Williams (1959) considers two competing linear regression models for the maximum compression strength parallel to the grain for radiata pine. Both models are of the form

$$y_i = \alpha + \beta(x_i - \bar{x}) + \epsilon_i,$$

where $\epsilon_i \sim N(0, \sigma^2)$ and $i = 1, \ldots, 42$. Here $y$ is the maximum compression strength in pounds per square inch. The density (in pounds per cubic foot) of the radiata pine is considered a useful predictor, so model 1 uses density for $x$. Model 2 instead considers the density adjusted for resin content, which is associated with high density but not with strength.

This example is frequently used as a test problem in model choice (see for example Carlin and Chib (1995) and Friel and Pettitt (2008)). We use the standard uninformative normal and inverse gamma priors for this example along with the transformation $\phi = \log(\sigma^2)$ so that all parameters are on the real line and $\theta = [\alpha, \beta, \phi]$. The evidence can be computed using numerical estimation for both of the competing models. The log evidence is -309.9 for model 1 and -301.4 for model 2.

The LinReg function implements a data annealing approach to this example.

The LinRegLA function implements a likelihood annealing approach to this example.

The LinRegLA_adapt function implements a likelihood annealing approach to this example with adaptation of the temperature schedule, number of MCMC repeats and random walk covariance matrices.

Value

The LinReg function returns a list containing the final particle approximation to the target ($\theta$ and the corresponding weights) as well as the logarithm of the estimated model evidence.

The LinRegLA function returns a list containing the population of particles and their associates log likelihoods, log priors and weights at each iteration. The effective sample size at each of the iterations and several different estimates of the logarithm of the model evidence are also returned.

The LinRegLA_adapt function returns a list containing all of the same output as LinRegLA, in addition to the adaptively chosen temperature schedule and number of MCMC repeats.

Author(s)

Adam M. Johansen, Dirk Eddelbuettel and Leah F. South

References


Examples

```r
res <- LinReg(model=1, particles=1000, plot=TRUE)
res <- LinRegLA(model=1, particles=1000)
```
The `nonlinpmmh` function implements particle marginal Metropolis-Hastings for the non-linear state space model described in Section 3.1 of Andrieu et al. (2010).

### Usage

```r
nonlinpmmh(data, particles = 5000, iterations = 10000, burnin = 0, plot = FALSE)
```

### Arguments

- **data**: A vector of the observed data.
- **particles**: An integer specifying the number of particles in the particle filtering estimates of the likelihood.
- **iterations**: An integer specifying the number of MCMC iterations.
- **burnin**: The number of iterations to remove from the beginning of the MCMC chain (for plotting purposes only).
- **plot**: A boolean variable to determine whether to plot the posterior estimates and MCMC chain.

### Details

This example uses particle marginal Metropolis Hastings to estimate the standard deviation of the evolution and observation noise in the following non-linear state space model:

\[
x(n) = 0.5x(n - 1) + 25x(n - 1)/(1 + x(n - 1)^2) + 8\cos(1.2n) + e(n)
\]

\[
y(n) = x(n)^2/20 + f(n)
\]

where \(e(n)\) and \(f(n)\) are mutually-independent normal random variables of variances \(\text{var}_\text{evol}\) and \(\text{var}_\text{obs}\), respectively, and \(x(0) \sim N(0, 5)\).

Following Andrieu, Doucet and Holenstein (2010), the priors are \(\text{var}_\text{evol} IG(0.01, 0.01)\) and \(\text{var}_\text{obs} IG(0.01, 0.01)\) where IG is the inverse gamma distribution.

Data can be simulated from the model using `simNonlin`.

### Value

A `data.frame` containing the chain of simulated \(\sigma_v\) and \(\sigma_w\) values, as well as the corresponding log likelihood estimates and log prior values.
Author(s)
Adam M. Johansen, Dirk Eddelbuettel and Leah F. South

References

See Also
simNonlin for a function to simulate from the model and pfNonlinBS for a simple bootstrap particle filter applied to a similar non-linear state space model.

Examples

## Not run:
```
sim <- simNonlin(len=500, var_init=5, var_evol=10, var_obs=1, cosSeqOffset=0)
res <- nonLinPMH(sim$data, particles=5000, iterations=50000, burnin=10000, plot=TRUE)
```

## End(Not run)

---

pfLineartBS  
Particle Filter Example

Description
The pfLineartBS function provides a simple example for ReppSMC. It is based on the first example in SMCTC and the discussion in Section 5.1 of Johansen (2009). A simple ‘vehicle tracking’ problem of 100 observations is solved with 1000 particles.

The pfLineartBSOnlinePlot function provides a simple default ‘online’ plotting function that is invoked during the estimation process.

The simLineart function simulates data from the model.

Usage
```
pfLineartBS(data, particles=1000, plot=FALSE, onlinePlot)
pfLineartBSOnlinePlot(xm, ym)
simLineart(len)
```

Arguments
data  A two-column matrix or dataframe containing x and y values. The default data set from Johansen (2009) is used as the default if no data is supplied.
particles  An integer specifying the number of particles.
plot  A boolean variable describing whether plot should illustrate the estimated path along with the data.
onlinePlot  A user-supplied callback function which is called with the x and y position vectors during each iteration of the algorithm; see pfExOnlinePlot for a simple example.

xm  Vector with x position.

ym  Vector with y position.

len  Length of sequence to simulate

Details

The pfLineartBS function provides a simple example for RcppSMC. The model is linear with t-distributed innovations. It is based on the pf example in the SMCTC library, and discussed in the Section 5.1 of his corresponding paper (Johansen, 2009). simLineart simulates from the model.

Using the simple pfExOnlinePlot function illustrates how callbacks into R, for example for plotting, can be made during the operation of SMC algorithm.

Value

The pfLineartBS function returns a data.frame containing as many rows as in the input data, and four columns corresponding to the estimated x and y coordinates as well as the estimated velocity in these two directions.

The simLineart function returns a list containing the vector of states and the associated vector of observations.

Author(s)

Adam M. Johansen and Dirk Eddelbuettel

References


See Also

The SMCTC paper and code at http://www.jstatsoft.org/v30/i06/paper.

Examples

```
res <- pfLineartBS(plot=TRUE)
if (!interactive()) ## if not running R CMD check etc
  res <- pfLineartBS(onlinePlot=pfLineartBSOnlinePlot)
```
pfNonlinBS  Nonlinear Bootstrap Particle Filter (Univariate Non-Linear State Space Model)

Description

The pfNonlinBS function provides a simple example for RcppSMC. It is a simple “bootstrap” particle filter which employs multinomial resampling after each iteration applied to the ubiquitous "nonlinear state space model" following Gordon, Salmond and Smith (1993).

Usage

pfNonlinBS(data, particles=500, plot=FALSE)

Arguments

data  A vector variable containing the sequence of observations.
particles  An integer specifying the number of particles.
plot  A boolean variable describing whether a plot should illustrate the (posterior mean) estimated path along with one and two standard deviation intervals.

Details

The pfNonlinBS function provides a simple example for RcppSMC. It is based on a simple nonlinear state space model in which the state evolution and observation equations are: x(n) = 0.5 x(n-1) + 25 x(n-1) / (1 + x(n-1)^2) + 8 cos(1.2(n-1)) + e(n) and y(n) = x(n)^2 / 20 + f(n) where e(n) and f(n) are mutually-independent normal random variables of variances 10.0 and 1.0, respectively. A bootstrap proposal (i.e. sampling from the state equation) is used, together with multinomial resampling after each iteration.

Value

The pfNonlinBS function returns two vectors, the first containing the posterior filtering means; the second the posterior filtering standard deviations.

Author(s)

Adam M. Johansen, Dirk Eddelbuettel and Leah F. South

References


See Also

simNonlin for a function to simulate from the model and nonLinPMH for an example of particle marginal Metropolis Hastings applied to a non-linear state space model.
**Examples**

```r
sim <- simNonlin(len=50)
res <- pfNonlinBS(sim$data, particles=500, plot=TRUE)
```

---

**radiata**

Radiata pine dataset (linear regression example)

---

**Description**

This dataset was originally presented in Table 5.1 of Williams (1959) where two non-nested linear regression models were considered.

**Usage**

```r
radiata
```

**Format**

A data frame with 42 rows and three variables:

- **y**: Maximum compression strength (response) in pounds per square inch
- **x1**: Density (predictor 1) in pounds per cubic foot
- **x2**: Adjusted density (predictor 2) in pounds per cubic foot

**Source**


---

**simNonlin**

Simulates from a simple nonlinear state space model.

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**Description**

The `simNonlin` function simulates data from the models used in `pfNonlinBS` and `nonLinPMMH`.

**Usage**

```r
simNonlin(len = 50, var_init = 10, var_evol = 10, var_obs = 1, cosSeqOffset = -1)
```
Arguments

- **len**: The length of data sequence to simulate.
- **var_init**: The variance of the noise for the initial state.
- **var_evol**: The variance of the noise for the state evolution.
- **var_obs**: The variance of the observation noise.
- **cosSeqOffset**: This is related to the indexing in the cosine function in the evolution equation. A value of -1 can be used to follow the specification of Gordon, Salmond and Smith (1993) and 0 can be used to follow Andrieu, Doucet and Holenstein (2010).

Details

The `simNonlin` function simulates from a simple nonlinear state space model with state evolution and observation equations:

\[
    x(n) = 0.5x(n-1) + 25x(n-1)/(1 + x(n-1)^2) + 8\cos(1.2(n + \text{cosSeqOffset})) + e(n) \\
    y(n) = x(n)^2/20 + f(n)
\]

where \( e(n) \) and \( f(n) \) are mutually-independent normal random variables of variances \( \text{var_evol} \) and \( \text{var_obs} \), respectively, and \( x(0) \sim \mathcal{N}(0, \text{var_init}) \).

Different variations of this model can be found in Gordon, Salmond and Smith (1993) and Andrieu, Doucet and Holenstein (2010). A \text{cosSeqOffset} of -1 is consistent with the former and 0 is consistent with the latter.

Value

The `simNonlin` function returns a list containing the state and data sequences.

Author(s)

Adam M. Johansen, Dirk Eddelbuettel and Leah F. South

References


See Also

- `pfNonlinBS` for a simple bootstrap particle filter applied to this model and `nonlinPMMH` for particle marginal Metropolis Hastings applied to estimating the standard deviation of the state evolution and observation noise.
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