Kriging Demystified Lachlan Astfalck What's going on under the hood of our favourite interpol

John

What is it, why do we care?

- Kriging is one of the most influential interpolation methods in statistics, geosciences, engineering, and anything else that needs interpolation.
	-

If you've asked SPSS or GIS to interpolate something before it's probably using Kriging or something related.

The multiple regression procedure for arriving at the *best linear unbiased* [predictor] or *best linear weighted moving average* [predictor] of the ore grade of an ore block (of any size) by assigning an optimum set of weights to all the available and relevant data inside and outside the ore block

Danie G. Krige

The multiple regression procedure for arriving at the *best linear unbiased* [predictor] or *best linear weighted moving average* [predictor] of the ore grade of an ore block (of any size) by assigning an optimum set of weights to all the available and relevant data inside and outside the ore block

Danie G. Krige

Given a covariance structure, Kriging estimates the unknown randomprocess mean with the **best linear unbiased estimator**.

Georges Matheron

Given a covariance structure, Kriging estimates the unknown randomprocess mean with the **best linear unbiased estimator**.

Georges Matheron

"Everything is related to everything else, but near things are more related than distant things" - Tobler's First Law of Geography

Building up interpolation

Building up interpolation

Building up interpolation

Tobler's First Law

It is more desirable to predict from points closer rather than points further away

×

 x_{x}

XX

×

х

 \times^{X}

×

×

Sensible interpolation methods include…

- Regression methods
- Bi-linear interpolation
- Inverse distance weighting
- Nearest neighbour predictions
- Spline interpolation
- **Kriging**

be thought of as realisations from a latent stochastic process.

Denote by s_i the spatial locations and $Z(s_i)$ the observed data that may

be thought of as realisations from a latent stochastic process.

Denote the covariance between any two points as $cov(Z(s), Z(s')) \equiv$. *C*(*s*,*s*′)

Denote by s_i the spatial locations and $Z(s_i)$ the observed data that may

be thought of as realisations from a latent stochastic process.

Denote the covariance between any two points as $cov(Z(s), Z(s')) \equiv$. *C*(*s*,*s*′)

We are going to focus on predicting the stochastic process, $Z\!\left(s_0\right)$, at a single location, S_0 .

Denote by s_i the spatial locations and $Z(s_i)$ the observed data that may

- Denote by s_i the spatial locations and $Z(s_i)$ the observed data that may be thought of as realisations from a latent stochastic process.
- Denote the covariance between any two points as $cov(Z(s), Z(s')) \equiv$. *C*(*s*,*s*′)
- We are going to focus on predicting the stochastic process, $Z\!\left(s_0\right)$, at a single location, S_0 .
- We're going to assume all data have point support.

a weighted linear average of the observed data that minimises the mean-squared error

We want the *best linear unbiased predictor* of $Z(s_0)$. This is given by

n ∑ *i*=1 $a_i Z(s_i) - k$ $\overline{}$ 2

Cranking out the math Minimising this objective yields where $\mathbf{c} \equiv (C(s_0, s_1), ..., C(s_0, s_n))'$ and $C_{i,j} \equiv C(s_i, s_j)$. $a = c'$ C^{-1} $k = E(Z(s_0)) + c$ ′ $C^{-1}E(Z)$

(we're about to go through why…)

We may thus say that the optimal predictor of $Z(s_0)$ is

$$
Z^*(s_0) = E\left(Z(s)\right)
$$

with prediction error

 $E\left(\left(Z(s_0) - Z^*(s_0) \right) \right)$

$Z^*(s_0) = E(Z(s_0)) + c'C(Z - E(Z))$

2 \int = $C(s_0, s_0) - c'$ *C*−¹ c

First we need some basic identities:

$$
E\left(x^2\right) = v
$$

-
- $) = var(x) + (E(x))$ 2
- $var(x + y) = var(x) + 2cov(x, y) + var(y)$
	- $cov(ax, y) = acov(x, y)$
		- $\text{var}(ax) = a^2 \text{var}(x)$
		- $var(x + c) = var(x)$

 $E\left(\left(\frac{Z(s_0)}{R}\right) - a^T Z - k\right)$ 2 \int = var $(Z(s_0) - a^TZ) + (E(Z(s_0) - a^TZ - k))$ 2

 $E\left(\left(\frac{Z(s_0)}{R}\right) - a^T Z - k\right)$ 2

and so $k = E(Z(s_0)) - a^T E(Z)$

$$
\Big) = \text{var}\left(Z(s_0) - a^T Z\right) + \left(E\left(Z(s_0) - a^T Z - k\right)\right)^2
$$

$$
- a^T E(Z) \text{ so that } \left(E\left(Z(s_0) - a^T Z - k\right)\right)^2 = 0.
$$

 $E\left(\left(\frac{Z(s_0)}{R}\right) - a^T Z - k\right)$ 2

$$
\Big) = \text{var}\left(Z(s_0) - a^T Z\right) + \left(E\left(Z(s_0) - a^T Z - k\right)\right)^2
$$

and so
$$
k = E(Z(s_0)) - a^T E(Z)
$$
 so that $(E(Z(s_0) - a^T Z - k))^{2} = 0$.
var $(Z(s_0) - a^T Z) = \text{var } (Z(s_0)) - 2\text{cov } (Z(s_0), Z)$ a + a^Tvar (Z) a

$$
E\left(\left(Z(s_0) - a^T Z - k\right)^2\right) = \text{var}\left(Z(s_0) - a^T Z\right) + \left(E\left(Z(s_0) - a^T Z - k\right)\right)^2
$$

and so $k = E(Z(s_0)) - a^T E(Z)$

so that
$$
\left(E\left(Z(s_0) - a^T Z - k \right) \right)^2 = 0.
$$

var
$$
(Z(s_0) - a^T Z) = \text{var}(Z(s_0)) - 2\text{cov}(Z(s_0), Z) a + a^T \text{var}(Z) a
$$

Differentiating with respect to a:

 $E\left(\left(\frac{Z(s_0)}{R}\right) - a^T Z - k\right)$ 2

and so $k = E(Z(s_0)) - a^T E(Z)$

 $var(Z(s_0) - a^T Z) = var(Z(s_0))$

$$
\Big) = \text{var}\left(Z(s_0) - a^T Z\right) + \left(E\left(Z(s_0) - a^T Z - k\right)\right)^2
$$

so that
$$
(E(Z(s_0) - a^TZ - k))^2 = 0
$$
.

$$
)\bigg(-2\text{cov}\left(Z(s_0),Z\right)a+a^Tvar\left(Z\right)a
$$

$$
Z\big) + 2a^T \text{var} (Z) = 0
$$

Differentiating with respect to a:

 -2 cov $(Z(s_0), \overline{z})$

$$
E\left(\left(Z(s_0) - a^T Z - k\right)^2\right) = \text{var}\left(Z(s_0) - a^T Z\right) + \left(E\left(Z(s_0) - a^T Z - k\right)\right)^2
$$

and so
$$
k = E(Z(s_0)) - a^T E(Z)
$$
 so that $(E(Z(s_0) - a^T Z - k))^2 = 0$.

var
$$
(Z(s_0) - a^T Z) = \text{var}(Z(s_0)) - 2\text{cov}(Z(s_0), Z) a + a^T \text{var}(Z) a
$$

Differentiating with respect to a:

$$
-2\text{cov}\left(Z(s_0), Z\right) + 2a^T \text{var}\left(Z\right) = 0
$$

and so $a^T = \text{cov}\left(Z(s_0), Z\right) \text{var}\left(Z\right)^{-1}$

But how do we figure out covariance?

WEIGOME TOSTATISTICS

But how do we figure out covariance?

Recall that this squared distance is very reminiscent of the definition of variance: var[x] = $E((x - E[x])^2)$. 2)

variance: var[x] = $E((x - E[x])^2)$.

- Recall that this squared distance is very reminiscent of the definition of 2)
- A mathematical interpretation of Tobler's Law is that points close to

each other have a high covariance (and thus observing one point resolves much of the uncertainty in another).

variance: var[x] = $E((x - E[x])^2)$.

- Recall that this squared distance is very reminiscent of the definition of 2)
- A mathematical interpretation of Tobler's Law is that points close to
	-

each other have a high covariance (and thus observing one point resolves much of the uncertainty in another).

The semivariogram is a way of describing the expected variance between two points as a function of distance

variance: var[x] = $E((x - E[x])^2)$.

- Recall that this squared distance is very reminiscent of the definition of 2)
- A mathematical interpretation of Tobler's Law is that points close to
	-
	-

each other have a high covariance (and thus observing one point resolves much of the uncertainty in another).

The semivariogram is a way of describing the expected variance between two points as a function of distance

The covariance function describes how two points co-vary as a function of distance

The covariance function Partial Sill · Nugget $C\left(d(s_i, s_j)\right)$)

Once we have a fit semivariogram or covariance function we're good to go

$\hat{\gamma}(h) =$ 1 *nh* ∑ s_i , $s_k \in N(h)$

for some choice of $h = |s_i - s_k|$

 $(Z(s_i) - Z(s_k))$ 2

Empirically fitting semivariograms is appropriate for pedagogy but is quite an 'old' way of solving the problem.

quite an 'old' way of solving the problem.

- Empirically fitting semivariograms is appropriate for pedagogy but is
- More often covariance functions are usually specified and fit (generally

via likelihood methods) manually or automatically.

quite an 'old' way of solving the problem.

- Empirically fitting semivariograms is appropriate for pedagogy but is
- More often covariance functions are usually specified and fit (generally
- This is most likely what is happening in the background of an kriging

via likelihood methods) manually or automatically.

software that you are using.

quite an 'old' way of solving the problem.

- Empirically fitting semivariograms is appropriate for pedagogy but is
- More often covariance functions are usually specified and fit (generally
- This is most likely what is happening in the background of an kriging
	-

via likelihood methods) manually or automatically.

software that you are using.

Be aware of what covariance function is being assumed - different functions yield drastically different interpolations.

-
-
-
-
-
-

1. We have the data

- 1. We have the data
- 2. We have a covariance function that models the data well

- 1. We have the data
- 2. We have a covariance function that models the data well
- 3. We're all over the mathematical theory

- 1. We have the data
- 2. We have a covariance function that models the data well
- 3. We're all over the mathematical theory
- 4. Now we're ready to predict!

- 1. We have the data
- 2. We have a covariance function that models the data well
- 3. We're all over the mathematical theory
- 4. Now we're ready to predict!

$$
E\left(Z^*(s_0)\right) = E\left(Z\right)
$$

$E(Z^*(s_0)) = E(Z(s_0)) + c'C(Z - E(Z))$

- 1. We have the data
- 2. We have a covariance function that models the data well
- 3. We're all over the mathematical theory
- 4. Now we're ready to predict!

$$
E(Z^*(s_0)) = E(Z(s_0)) + c'C(Z - E(Z))
$$

var $(Z^*(s_0)) = C(s_0, s_0) - c'C^{-1}c$

A rose by any other name…

Simple Kriging

Ordinary Kriging

Universal Kriging

Disjunctive Kriging

Linear Regression

Gaussian Processes

Kalman Filtering

Gaussian Markov Random Fields

Wiener-Kolmogorov Predictions

Spline Regression in Reproducing Kernel Hilbert Spaces

Bayes linear analysis

A rose by any other name…

Simple Kriging

Ordinary Kriging

Universal Kriging

Disjunctive Kriging

Linear Regression

Gaussian Processes

Kalman Filtering

The essence/ideas underpinning kriging are everywhere! If you're ever interpolating or regressing, be mindful of where it may be.

Gaussian Markov Random Fields

Wiener-Kolmogorov Predictions

Spline Regression in Reproducing Kernel Hilbert Spaces

Bayes linear analysis

What we haven't talked about

Stationarity, types of covariance functions and positive definiteness

Methods of inference

- Kriging with big data
- Assumptions of Gaussinity

"LISTEN, SCIENCE IS HARD. BUT I'M A SERIOUS PERSON DOING MY BEST."

"I HAD AN IDEA FOR HOU TO CLEAN UP THE DATA. WHAT DO YOU THINK?"

EXTEND IT AAAAAA!!"

CURVE-FITTING METHODS AND THE MESSAGES THEY SEND