



Interpolation with irregular support - examining a simplification

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Motivation interpolation with a support

- Increased interest in geostatistical methods for variables which has a support
- Examples:
 - Regionalisation of runoff variables
 - Health statistics
- Support can be spatial and/or temporal
- Methods includes integrals of variogram/covariance functions



Example: Predictions annual mean flow

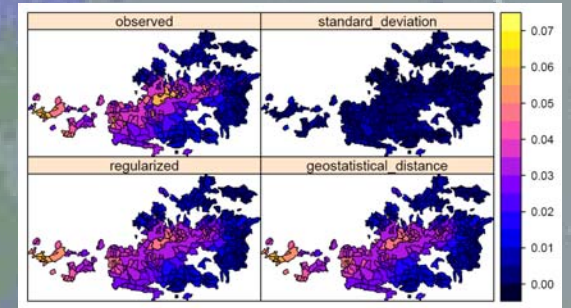
- Annual mean flow from 383 stations in Austria
- Top-kriging method (Skøien et al, 2006) used for predictions at locations without observations
- Geostatistical distance used instead of regularization as in original

Comparison variogram values

- Sample variogram values (binned) estimated for annual mean
- Figures below show observed versus fitted semivariances for the two methods
- Models are qualitatively similar but give large scatter – probably effect of some violation of stationarity assumptions

Cross-validation of predictions

- Ghosh approximation does not tend to be more stable than for Top-kriging
- Some very large weights observed
- Below: Comparison of predictions from the two methods, compared with observations and standard deviations
- Units: m³/s/km²



Difficulties with regularization

- Integrations can be slow and lead to numerical instabilities
- Fast and robust methods necessary for real-time interpolation, as developed within the INTAMAP project (www.intamap.org)
- Possible solution: Replacing the integral with an approximation, suggested by Gottschalk (1993)

Approximation

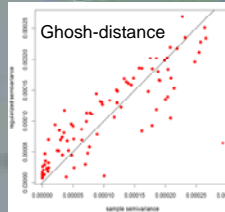
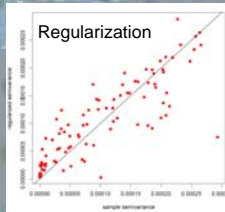
- Suggested by Gottschalk (1993) - replace integration with expectations using Taylor expansion
- The covariance can be expressed through the correlogram:

$$Cov(Z_1, Z_2) = \int \int_{A_1, A_2} Cov(\mathbf{x}_1 - \mathbf{x}_2) d\mathbf{x}_1 d\mathbf{x}_2 = E[Cov(d)] = \sigma^2 E[\rho(d)]$$

- Where d represents distances between points in the two catchments
- The approximation can similarly be derived for the variogram:

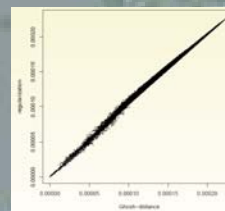
$$\gamma_{12} = 0.5 * Var(z(A_1) - z(A_2)) = \gamma_p(E(|\mathbf{x}_{11} - \mathbf{x}_{22}|)) - 0.5 * [\gamma_p(E(|\mathbf{x}_{11} - \mathbf{x}_{12}|)) + \gamma_p(E(|\mathbf{x}_{21} - \mathbf{x}_{22}|))] = \gamma_p(g_{db}) - 0.5[\gamma_p(g_{d1}) + \gamma_p(g_{d2})]$$

- g_{d1} , g_{d2} and g_{db} represent the expected distances between points within the first catchment, the second catchment, and between the two catchments, respectively
- Approximation can generally be referred to as Ghosh approximation from Ghosh (1951)



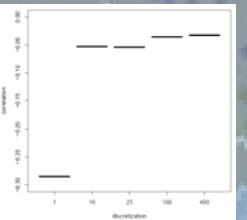
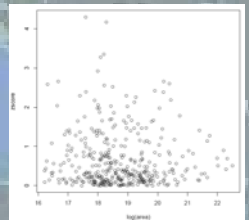
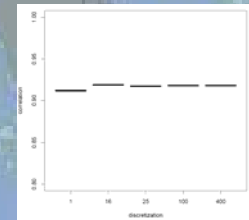
Above: Comparison between sample semivariances and fitted semivariances for regularization and Ghosh-distance

Right: Comparison between estimated semivariogram values from same point variogram for regularization and Ghosh-distance



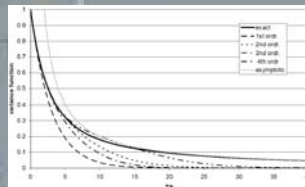
Effect of number of discretization points

- Number of discretization points limited importance for correlation between observations and predictions (left)
- Correlation between zscore (residual/kriging standard deviation) should ideally be zero
- Strong (negative) correlation between zscore and area for point kriging (middle)
- Correlation decreasing with increasing number of discretization points (right)



Example temporal autocorrelation

- Exponential correlation function
- Different orders of Taylor expansion
- T = temporal support relative to correlation length



Time consumption

(Just indicative)

Max number of points	Regularization Time (seconds)	Ghosh-distance Time (seconds)
16	19	23
25	24	41
100	135	470
400	1821	7423

Conclusions

- Approximation works in many cases
- Stability of kriging matrix needs to be further checked
- Use of Ghosh-approximation only possibility for real time mapping
- Calculation of ghosh-distances slow, but can be done before real-time mapping takes place