



Bayesian Melding in Urban Simulations

Hana Ševčíková

Center for Urban Simulation and Policy Analysis
University of Washington, Seattle

UTIA Dept. of Pattern Recognition, Praha

www.stat.washington.edu/hana, www.urbansim.org

Joint work with Adrian Raftery and Paul Waddell

2nd International Workshop DAR, Třešř 2006



Outline

- Motivation



Outline



- Motivation
- Description of the computer model UrbanSim



Outline



- Motivation
- Description of the computer model UrbanSim
- Methodology of applying Bayesian melding to UrbanSim



Outline



- Motivation
- Description of the computer model UrbanSim
- Methodology of applying Bayesian melding to UrbanSim
- Results



Outline



- Motivation
- Description of the computer model UrbanSim
- Methodology of applying Bayesian melding to UrbanSim
- Results
- Summary

Motivation

- Target: Simulation models for land use, transportation and environmental planning



Motivation



- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty

Motivation

- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data,



Motivation



- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data, systematic errors,



Motivation



- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data, systematic errors, model structure,

Motivation

- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data, systematic errors, model structure, input parameters,



Motivation



- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data, systematic errors, model structure, input parameters, stochasticity



Motivation



- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data, systematic errors, model structure, input parameters, stochasticity
- They usually provide point predictions.



Motivation



- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data, systematic errors, model structure, input parameters, stochasticity
- They usually provide point predictions.
- Need for expressing uncertainty about model output quantities of policy interest.

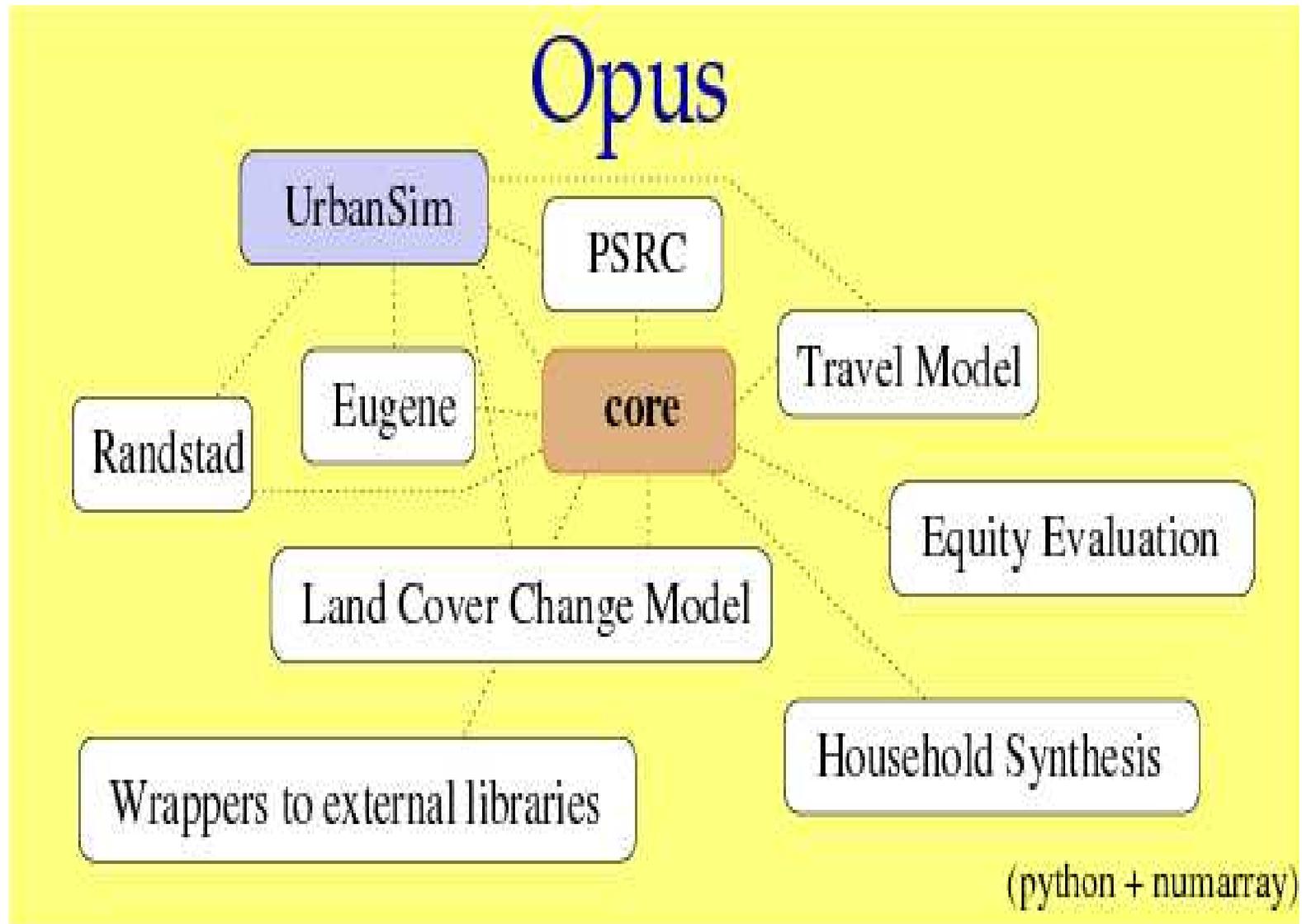
Motivation

- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data, systematic errors, model structure, input parameters, stochasticity
- They usually provide point predictions.
- Need for expressing uncertainty about model output quantities of policy interest.
- Multiple runs not satisfactory.

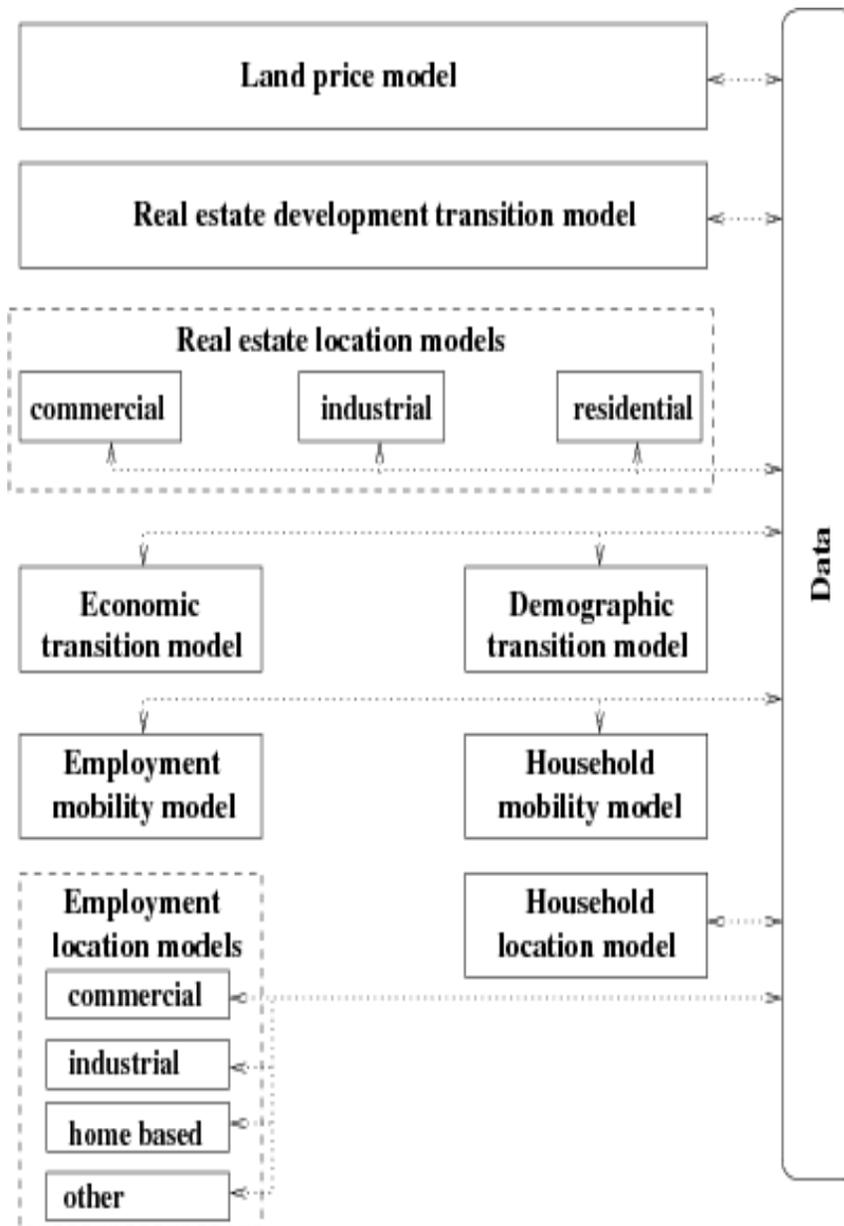
Motivation

- Target: Simulation models for land use, transportation and environmental planning
- Such models are subject to uncertainty
 - ◆ measurement errors in input data, systematic errors, model structure, input parameters, stochasticity
- They usually provide point predictions.
- Need for expressing uncertainty about model output quantities of policy interest.
- Multiple runs not satisfactory.
- **Method: Bayesian Melding**

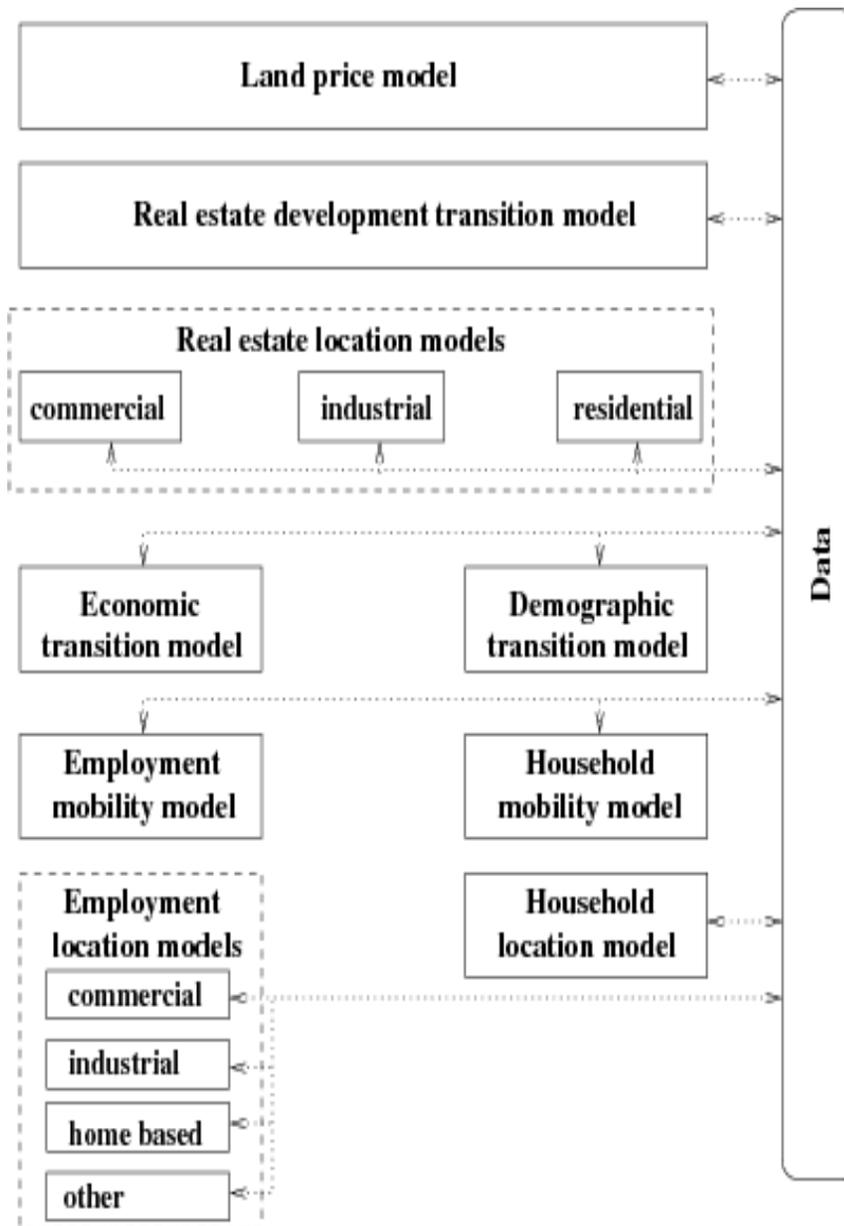
Open Platform for Urban Simulation



UrbanSim

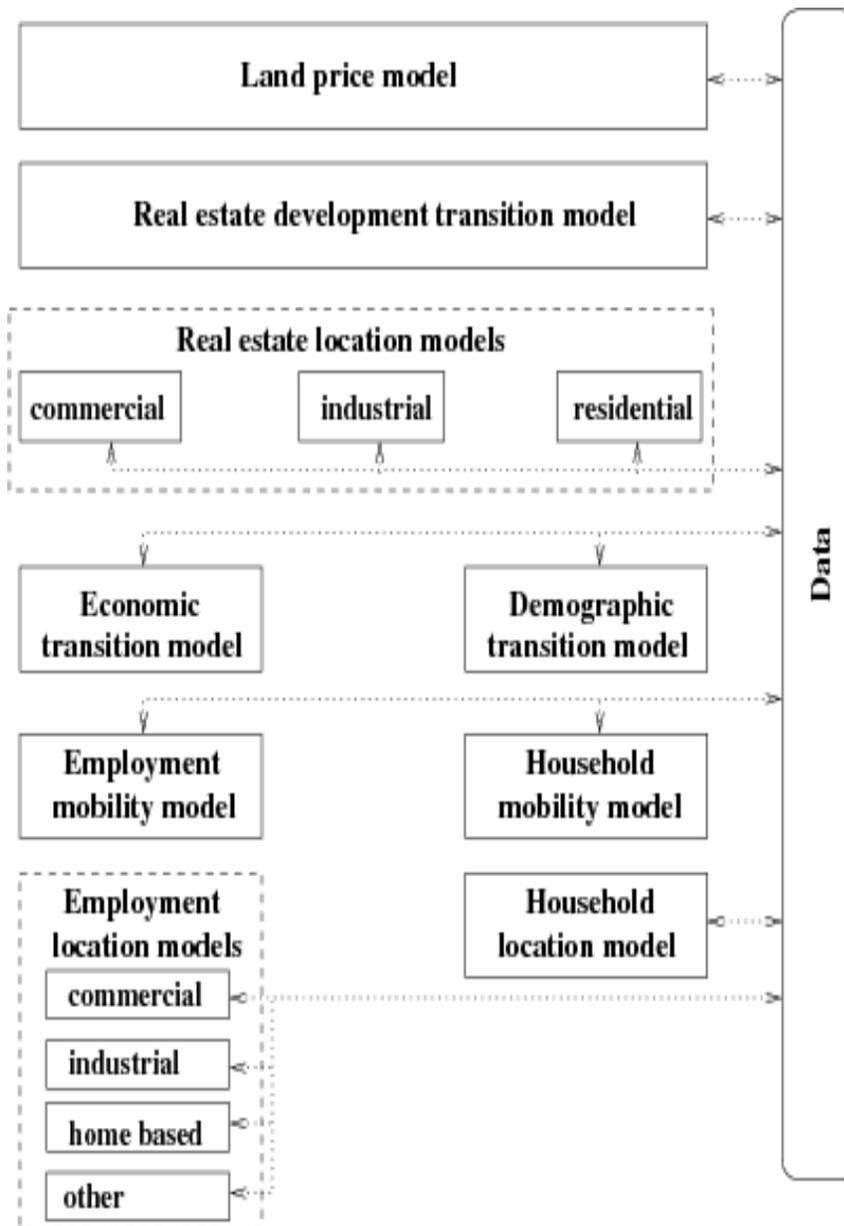


UrbanSim



Uncertainty:
75 submodels (51 stochastic)

UrbanSim

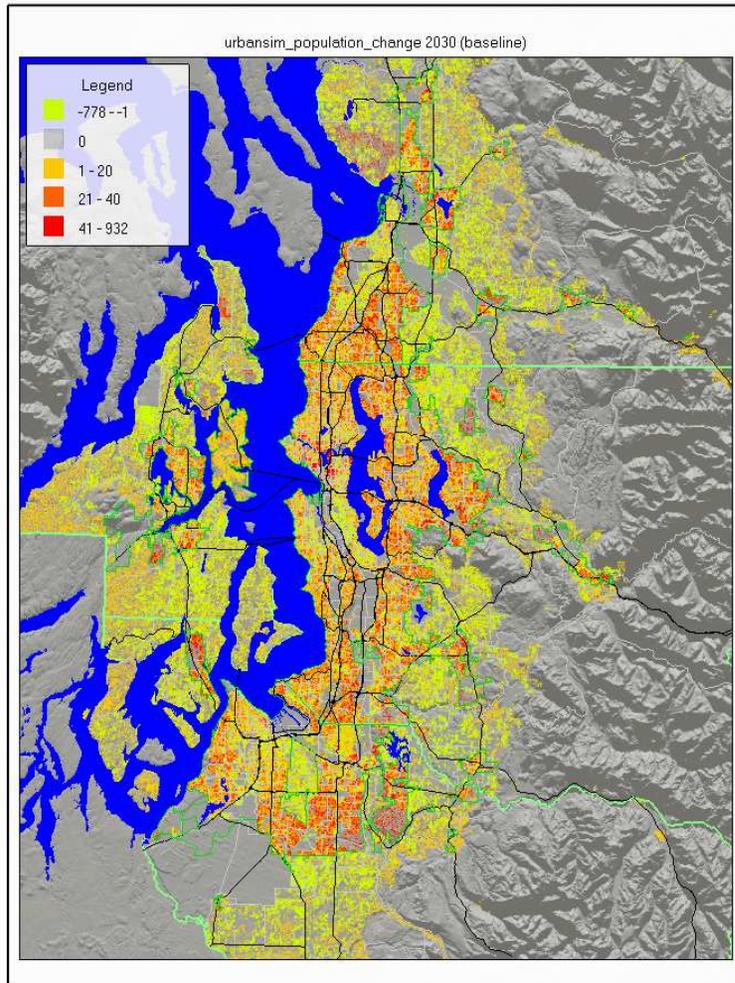


Uncertainty:

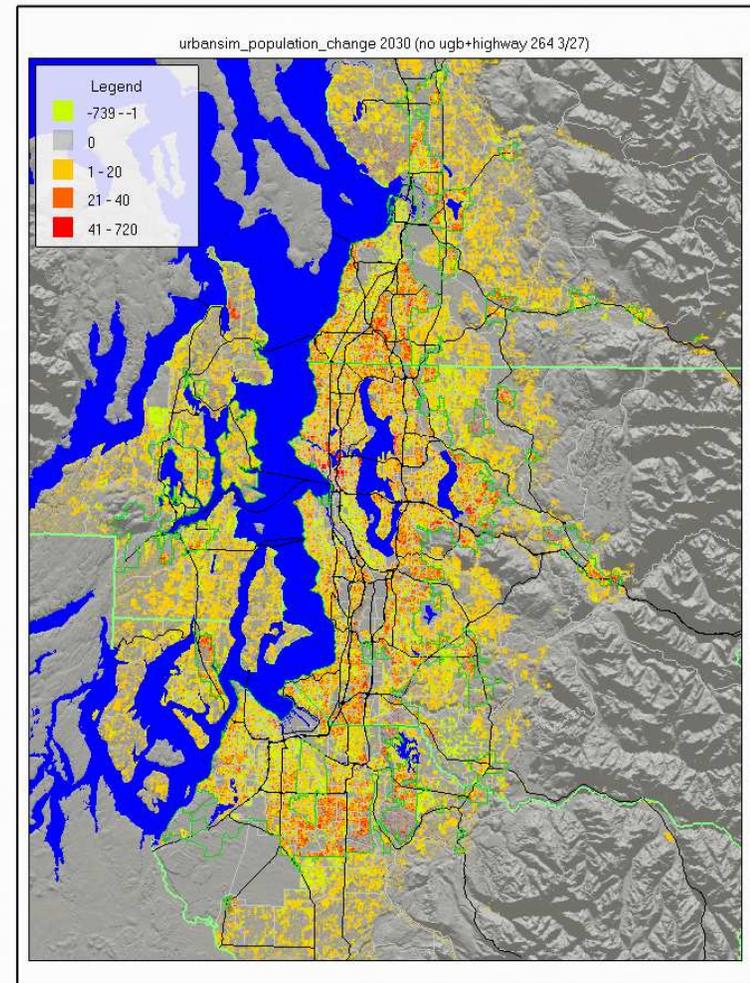
75 submodels (51 stochastic)
972 input par. for PSRC appl.

Population change in Puget Sound area (30 years prediction)

baseline



no UGB + highway



Bayesian Melding notation

Θ collection of model inputs

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information
- Ψ quantities of policy interest

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information
- Ψ quantities of policy interest
- y observed data

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information
- Ψ quantities of policy interest
- y observed data

$$\Phi = M_{\Phi}(\Theta)$$

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information
- Ψ quantities of policy interest
- y observed data

$$\Phi = M_{\Phi}(\Theta)$$

$$\Psi = M_{\Psi}(\Theta, \Phi) = M_{\Psi}(\Theta, M_{\Phi}(\Theta))$$

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information
- Ψ quantities of policy interest
- y observed data

$$\Phi = M_{\Phi}(\Theta)$$

$$\Psi = M_{\Psi}(\Theta, \Phi) = M_{\Psi}(\Theta, M_{\Phi}(\Theta))$$

$$L(\Phi) = \text{Prob}(y|\Phi)$$

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information
- Ψ quantities of policy interest
- y observed data

$$\Phi = M_{\Phi}(\Theta)$$

$$\Psi = M_{\Psi}(\Theta, \Phi) = M_{\Psi}(\Theta, M_{\Phi}(\Theta))$$

$$L(\Phi) = \text{Prob}(y|\Phi)$$

$$L(\Theta) = \text{Prob}(y|M_{\Phi}(\Theta))$$

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information
- Ψ quantities of policy interest
- y observed data

$$\Phi = M_{\Phi}(\Theta)$$

$$\Psi = M_{\Psi}(\Theta, \Phi) = M_{\Psi}(\Theta, M_{\Phi}(\Theta))$$

$$L(\Phi) = \text{Prob}(y|\Phi)$$

$$L(\Theta) = \text{Prob}(y|M_{\Phi}(\Theta))$$

$$\pi(\Theta) \propto q(\Theta)L(\Theta)$$

Bayesian Melding notation

- Θ collection of model inputs
- $q(\Theta)$ prior probability distribution of inputs
- Φ collection of model outputs about which we have information
- Ψ quantities of policy interest
- y observed data

$$\Phi = M_{\Phi}(\Theta)$$

$$\Psi = M_{\Psi}(\Theta, \Phi) = M_{\Psi}(\Theta, M_{\Phi}(\Theta))$$

$$L(\Phi) = \text{Prob}(y|\Phi)$$

$$L(\Theta) = \text{Prob}(y|M_{\Phi}(\Theta))$$

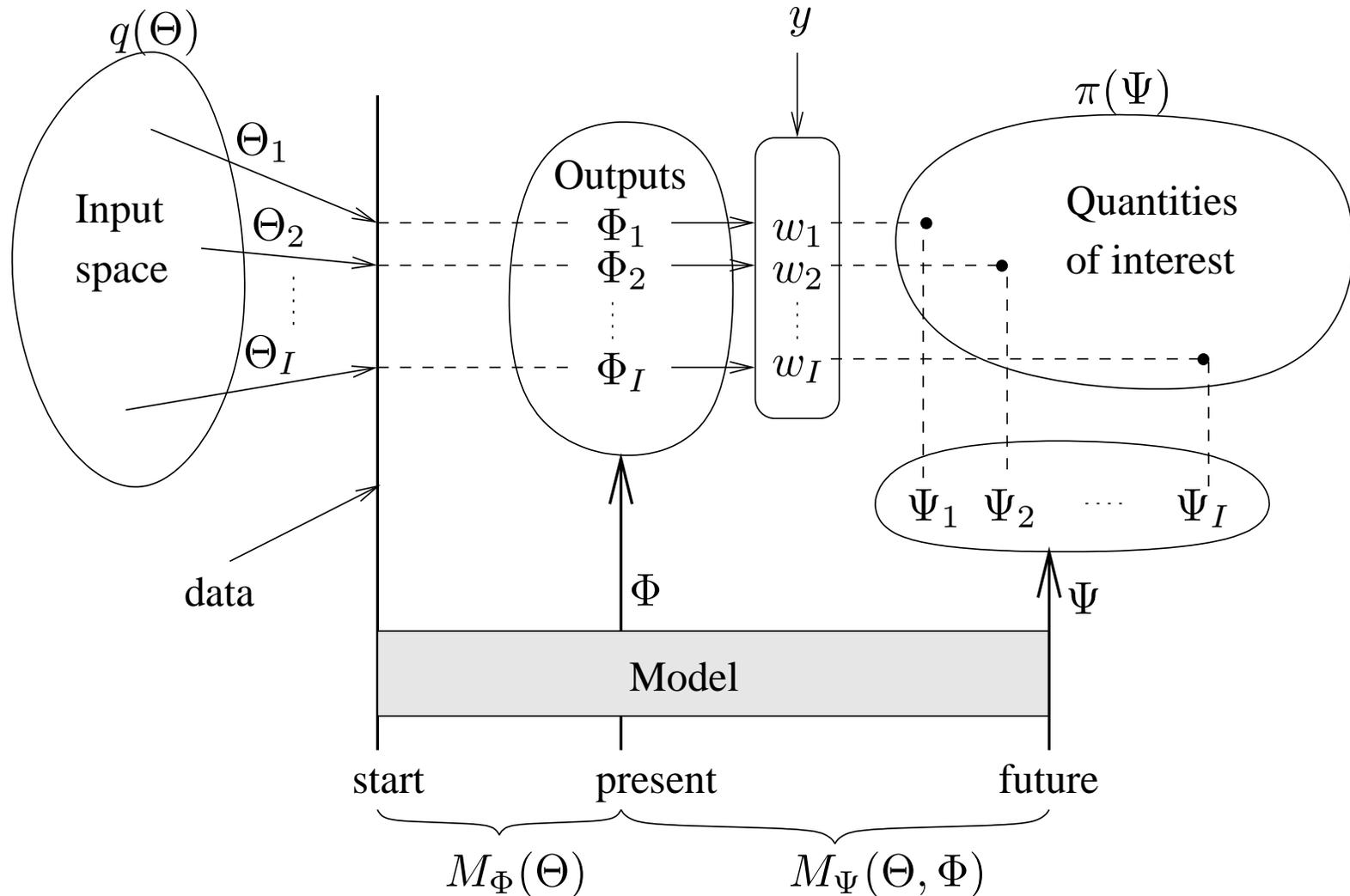
$$\pi(\Theta) \propto q(\Theta)L(\Theta) \rightarrow \text{yields } \pi(\Psi)$$

Bayesian Melding

For a deterministic model, based on Importance Sampling:

Bayesian Melding

For a deterministic model, based on Importance Sampling:





Computing the Posterior Distribution



For a stochastic model:

Computing the Posterior Distribution

For a stochastic model:

1. Draw a sample $\{\Theta_1, \dots, \Theta_I\}$ from $q(\Theta)$.

Computing the Posterior Distribution

For a stochastic model:

1. Draw a sample $\{\Theta_1, \dots, \Theta_I\}$ from $q(\Theta)$.
2. For each Θ_i , run the model J times with different seeds to obtain $\Phi_{ij}, j = 1, \dots, J$.

Computing the Posterior Distribution

For a stochastic model:

1. Draw a sample $\{\Theta_1, \dots, \Theta_I\}$ from $q(\Theta)$.
2. For each Θ_i , run the model J times with different seeds to obtain $\Phi_{ij}, j = 1, \dots, J$.
3. Compute weights $w_i = L(\bar{\Phi}_i)$ where $\bar{\Phi}_i = \frac{1}{J} \sum_{j=1}^J \Phi_{ij}$.

Computing the Posterior Distribution

For a stochastic model:

1. Draw a sample $\{\Theta_1, \dots, \Theta_I\}$ from $q(\Theta)$.
 2. For each Θ_i , run the model J times with different seeds to obtain $\Phi_{ij}, j = 1, \dots, J$.
 3. Compute weights $w_i = L(\bar{\Phi}_i)$ where $\bar{\Phi}_i = \frac{1}{J} \sum_{j=1}^J \Phi_{ij}$.
- Result: An approximate posterior distribution of inputs with values $\{\Theta_1, \dots, \Theta_I\}$ and probabilities proportional to $\{w_1, \dots, w_I\}$.

Computing the Posterior Distribution

For a stochastic model:

1. Draw a sample $\{\Theta_1, \dots, \Theta_I\}$ from $q(\Theta)$.
2. For each Θ_i , run the model J times with different seeds to obtain $\Phi_{ij}, j = 1, \dots, J$.
3. Compute weights $w_i = L(\bar{\Phi}_i)$ where $\bar{\Phi}_i = \frac{1}{J} \sum_{j=1}^J \Phi_{ij}$.
Result: An approximate posterior distribution of inputs with values $\{\Theta_1, \dots, \Theta_I\}$ and probabilities proportional to $\{w_1, \dots, w_I\}$.
4. Distributions of Φ and Ψ are finite mixtures:

$$\pi(\Phi) = \sum_{i=1}^I w_i p(\Phi | \Theta_i)$$

Computing the Posterior Distribution

For a stochastic model:

1. Draw a sample $\{\Theta_1, \dots, \Theta_I\}$ from $q(\Theta)$.
2. For each Θ_i , run the model J times with different seeds to obtain $\Phi_{ij}, j = 1, \dots, J$.
3. Compute weights $w_i = L(\bar{\Phi}_i)$ where $\bar{\Phi}_i = \frac{1}{J} \sum_{j=1}^J \Phi_{ij}$.
Result: An approximate posterior distribution of inputs with values $\{\Theta_1, \dots, \Theta_I\}$ and probabilities proportional to $\{w_1, \dots, w_I\}$.
4. Distributions of Φ and Ψ are finite mixtures:

$$\pi(\Phi) = \sum_{i=1}^I w_i p(\Phi|\Theta_i) \quad \pi(\Psi) = \sum_{i=1}^I w_i p(\Psi|\Theta_i)$$



Application to UrbanSim



- Test database: Eugene Springfield, OR



Application to UrbanSim



- Test database: Eugene Springfield, OR
- Baseyear data available for 1980.

Application to UrbanSim

- Test database: Eugene Springfield, OR
- Baseyear data available for 1980.
- We have observed the number of households in each zone in 1994, y_1, \dots, y_K ($K = 295$).

Application to UrbanSim

- Test database: Eugene Springfield, OR
- Baseyear data available for 1980.
- We have observed the number of households in each zone in 1994, y_1, \dots, y_K ($K = 295$).
- Prediction for 2000, Ψ_1, \dots, Ψ_K .

Application to UrbanSim

- Test database: Eugene Springfield, OR
- Baseyear data available for 1980.
- We have observed the number of households in each zone in 1994, y_1, \dots, y_K ($K = 295$).
- Prediction for 2000, Ψ_1, \dots, Ψ_K .
- start: 1980, present: 1994, future: 2000.

Likelihood and posterior distribution

We are interested in

$$w_i \propto p(y|\Theta_i) = \prod_{k=1}^K p(y_k|\Theta_i)$$

Likelihood and posterior distribution

We are interested in

$$w_i \propto p(y|\Theta_i) = \prod_{k=1}^K p(y_k|\Theta_i)$$

based on

$$\Phi_{ijk} = \mu_{ik} + \delta_{ijk}, \text{ where } \delta_{ijk} \stackrel{iid}{\sim} N(0, \sigma_\delta^2)$$

Likelihood and posterior distribution

We are interested in

$$w_i \propto p(y|\Theta_i) = \prod_{k=1}^K p(y_k|\Theta_i)$$

based on

$$\begin{aligned}\Phi_{ijk} &= \mu_{ik} + \delta_{ijk}, \text{ where } \delta_{ijk} \stackrel{iid}{\sim} N(0, \sigma_\delta^2) \\ (y_k|\Theta = \Theta_i) &= \mu_{ik} + a + \epsilon_{ik}, \text{ where } \epsilon_{ik} \stackrel{iid}{\sim} N(0, \sigma_i^2)\end{aligned}$$

Likelihood and posterior distribution

We are interested in

$$w_i \propto p(y|\Theta_i) = \prod_{k=1}^K p(y_k|\Theta_i)$$

based on

$$\Phi_{ijk} = \mu_{ik} + \delta_{ijk}, \text{ where } \delta_{ijk} \stackrel{iid}{\sim} N(0, \sigma_\delta^2)$$

$$(y_k|\Theta = \Theta_i) = \mu_{ik} + a + \epsilon_{ik}, \text{ where } \epsilon_{ik} \stackrel{iid}{\sim} N(0, \sigma_i^2)$$

Estimation of μ_{ik} , σ_δ^2 , σ_i^2 , and a done by approximate maximum likelihood.

Likelihood and posterior distribution (cont.)

$$y_k | \Theta_i \sim N(\hat{a} + \hat{\mu}_{ik}, v_i)$$

Likelihood and posterior distribution (cont.)

$$y_k | \Theta_i \sim N(\hat{a} + \hat{\mu}_{ik}, v_i) \quad \text{with} \quad v_i = \hat{\sigma}_i^2 + \frac{\hat{\sigma}_\delta^2}{J}$$

Likelihood and posterior distribution (cont.)

$$y_k | \Theta_i \sim N(\hat{a} + \hat{\mu}_{ik}, v_i) \quad \text{with} \quad v_i = \hat{\sigma}_i^2 + \frac{\hat{\sigma}_\delta^2}{J}$$

$$w_i \propto p(y | \Theta_i) =$$

Likelihood and posterior distribution (cont.)

$$y_k | \Theta_i \sim N(\hat{a} + \hat{\mu}_{ik}, v_i) \quad \text{with} \quad v_i = \hat{\sigma}_i^2 + \frac{\hat{\sigma}_\delta^2}{J}$$

$$w_i \propto p(y | \Theta_i) = \prod_{k=1}^K \frac{1}{\sqrt{2\pi v_i}} \exp \left[-\frac{1/2(y_k - \hat{a} - \hat{\mu}_{ik})^2}{v_i} \right]$$

Likelihood and posterior distribution (cont.)

$$y_k | \Theta_i \sim N(\hat{a} + \hat{\mu}_{ik}, v_i) \quad \text{with} \quad v_i = \hat{\sigma}_i^2 + \frac{\hat{\sigma}_\delta^2}{J}$$

$$w_i \propto p(y | \Theta_i) = \prod_{k=1}^K \frac{1}{\sqrt{2\pi v_i}} \exp \left[-\frac{1/2(y_k - \hat{a} - \hat{\mu}_{ik})^2}{v_i} \right]$$

$$\pi(\Psi_k) = \sum_{i=1}^I w_i N(\hat{a}b_a + \frac{1}{J} \sum_{j=1}^J \Psi_{ijk}, v_i b_v), \quad k = 1, \dots, K$$

Prior on inputs

- parameters estimated by multinomial logistic regression or linear regression:

Prior on inputs

- parameters estimated by multinomial logistic regression or linear regression:

$$MVN(\hat{\Theta}, \text{diag}(\text{SE}(\hat{\Theta})^2))$$

Prior on inputs

- parameters estimated by multinomial logistic regression or linear regression:

$$MVN(\hat{\Theta}, \text{diag} \left(SE(\hat{\Theta})^2 \right))$$

- mobility rates r :

Prior on inputs

- parameters estimated by multinomial logistic regression or linear regression:

$$MVN(\hat{\Theta}, \text{diag}(\text{SE}(\hat{\Theta})^2))$$

- mobility rates r :

$$N(\hat{r}, (\frac{\hat{r}(1 - \hat{r})}{n})^2) \quad \text{truncated at zero}$$

Prior on inputs

- parameters estimated by multinomial logistic regression or linear regression:

$$MVN(\hat{\Theta}, \text{diag}(\text{SE}(\hat{\Theta})^2))$$

- mobility rates r :

$$N(\hat{r}, (\frac{\hat{r}(1-\hat{r})}{n})^2) \quad \text{truncated at zero}$$

- control totals:

Prior on inputs

- parameters estimated by multinomial logistic regression or linear regression:

$$MVN(\hat{\Theta}, \text{diag}(\text{SE}(\hat{\Theta})^2))$$

- mobility rates r :

$$N(\hat{r}, (\frac{\hat{r}(1-\hat{r})}{n})^2) \quad \text{truncated at zero}$$

- control totals:

$$N(\hat{c}, 20V(\hat{c})), \quad V \text{ is estimated variance per year}$$

Simulation

- Run the model for 100 different outputs, 2 × with different seed
⇒ $I = 100$, $J = 2$ (results confirmed with $I = 1000$, $J = 3$)

Simulation

- Run the model for 100 different outputs, 2 × with different seed
⇒ $I = 100$, $J = 2$ (results confirmed with $I = 1000$, $J = 3$)
- Variances σ_{δ}^2 and σ_i^2 stabilized by applying the sqrt transform.

Simulation

- Run the model for 100 different outputs, $2 \times$ with different seed
 $\Rightarrow I = 100, J = 2$ (results confirmed with $I = 1000, J = 3$)
- Variances σ_δ^2 and σ_i^2 stabilized by applying the sqrt transform.
- From the results Φ_{ijk} we estimated \hat{a} , $\hat{\sigma}_\delta^2$, and $\hat{\sigma}_i^2$

Simulation

- Run the model for 100 different outputs, $2 \times$ with different seed
 $\Rightarrow I = 100, J = 2$ (results confirmed with $I = 1000, J = 3$)
- Variances σ_δ^2 and σ_i^2 stabilized by applying the sqrt transform.
- From the results Φ_{ijk} we estimated \hat{a} , $\hat{\sigma}_\delta^2$, and $\hat{\sigma}_i^2$
- Weights:

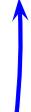
i	64	13	12	76	68	88	23	33(min)
w_i	0.8058	0.0883	0.0370	0.0217	0.0122	0.0116	0.0068	$4 \cdot 10^{-45}$

Simulation

- Run the model for 100 different outputs, $2 \times$ with different seed
 $\Rightarrow I = 100, J = 2$ (results confirmed with $I = 1000, J = 3$)
- Variances σ_δ^2 and σ_i^2 stabilized by applying the sqrt transform.
- From the results Φ_{ijk} we estimated \hat{a} , $\hat{\sigma}_\delta^2$, and $\hat{\sigma}_i^2$
- Weights:

i	64	13	12	76	68	88	23	33(min)
w_i	0.8058	0.0883	0.0370	0.0217	0.0122	0.0116	0.0068	$4 \cdot 10^{-45}$

$R = 0.93$



Simulation

- Run the model for 100 different outputs, $2 \times$ with different seed
 $\Rightarrow I = 100, J = 2$ (results confirmed with $I = 1000, J = 3$)
- Variances σ_δ^2 and σ_i^2 stabilized by applying the sqrt transform.
- From the results Φ_{ijk} we estimated \hat{a} , $\hat{\sigma}_\delta^2$, and $\hat{\sigma}_i^2$
- Weights:

i	64	13	12	76	68	88	23	33(min)
w_i	0.8058	0.0883	0.0370	0.0217	0.0122	0.0116	0.0068	$4 \cdot 10^{-45}$

$R = 0.93$ (pointing to 0.8058)

$R = 0.84$ (pointing to $4 \cdot 10^{-45}$)

Simulation

- Run the model for 100 different outputs, $2 \times$ with different seed
 $\Rightarrow I = 100, J = 2$ (results confirmed with $I = 1000, J = 3$)
- Variances σ_δ^2 and σ_i^2 stabilized by applying the sqrt transform.
- From the results Φ_{ijk} we estimated \hat{a} , $\hat{\sigma}_\delta^2$, and $\hat{\sigma}_i^2$
- Weights:

i	64	13	12	76	68	88	23	33(min)
w_i	0.8058	0.0883	0.0370	0.0217	0.0122	0.0116	0.0068	$4 \cdot 10^{-45}$

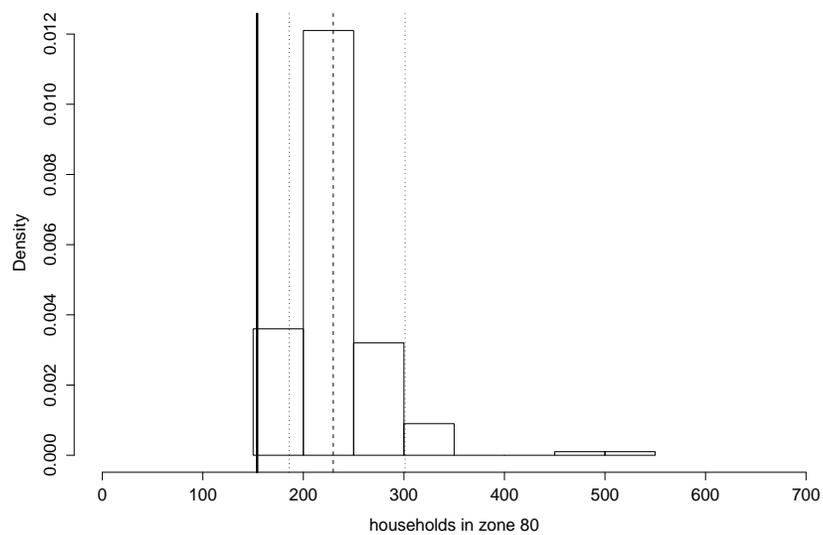
$R = 0.93$ (pointing to 0.8058)

$R = 0.84$ (pointing to $4 \cdot 10^{-45}$)

- propagation factors b_a and b_v set to $20/14 \left(\frac{2000-1980}{1994-1980} \right)$

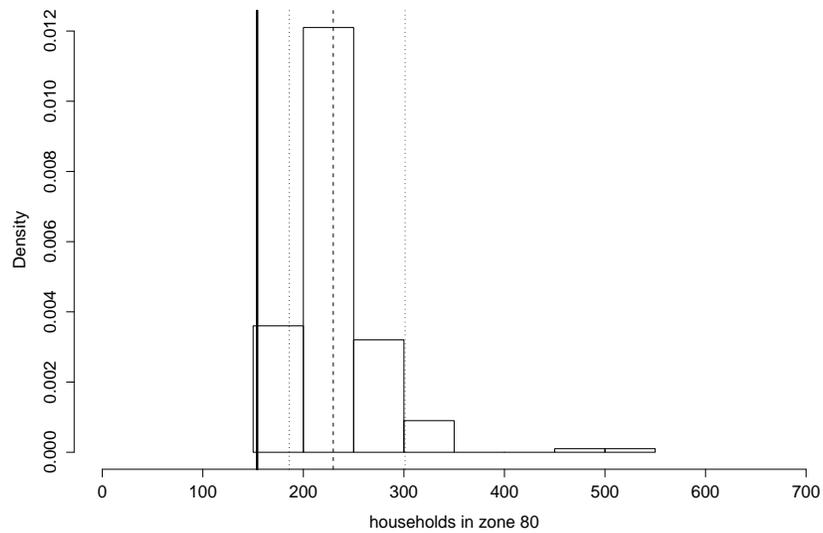
Results

Multiple runs

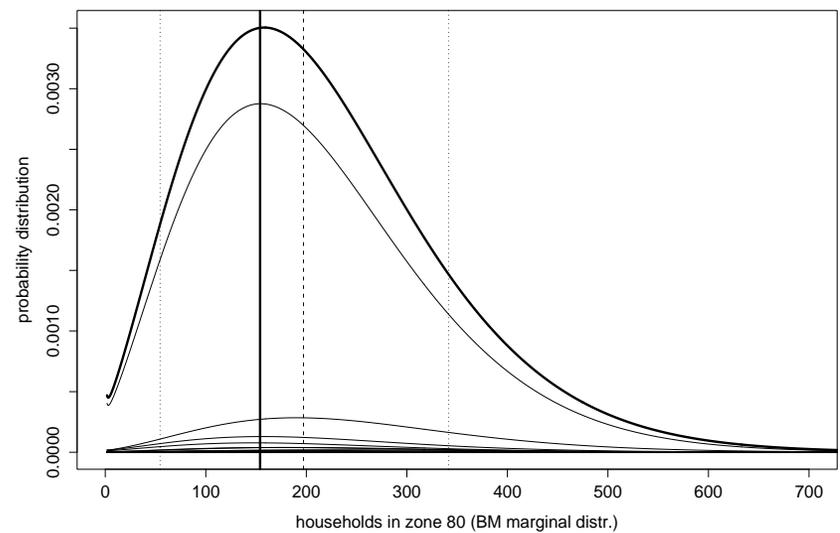


Results

Multiple runs

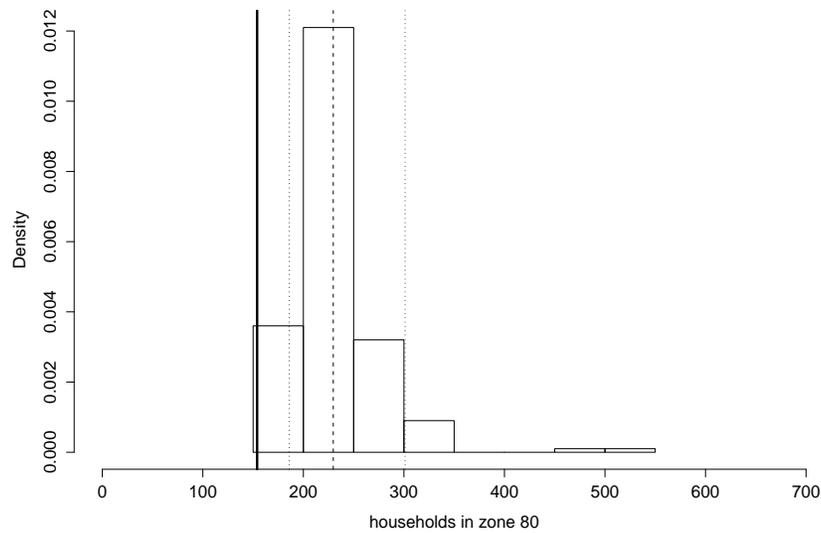


Bayesian melding

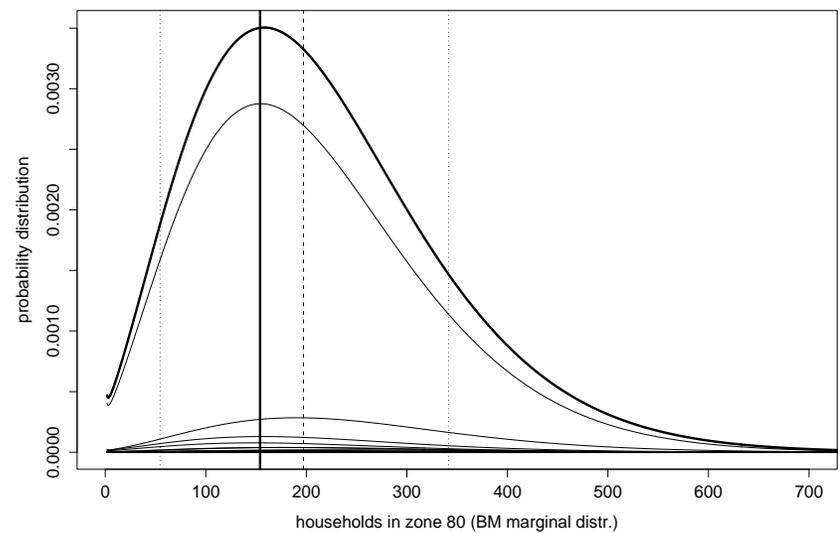


Results

Multiple runs



Bayesian melding



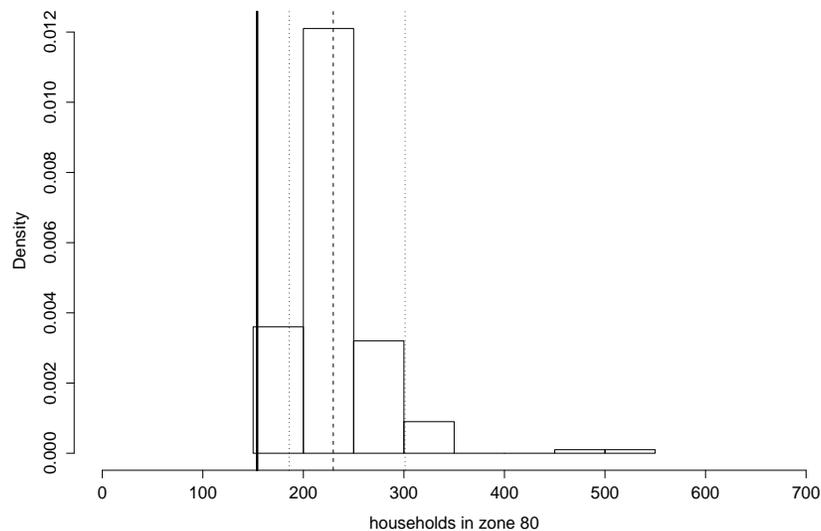
method

missed cases

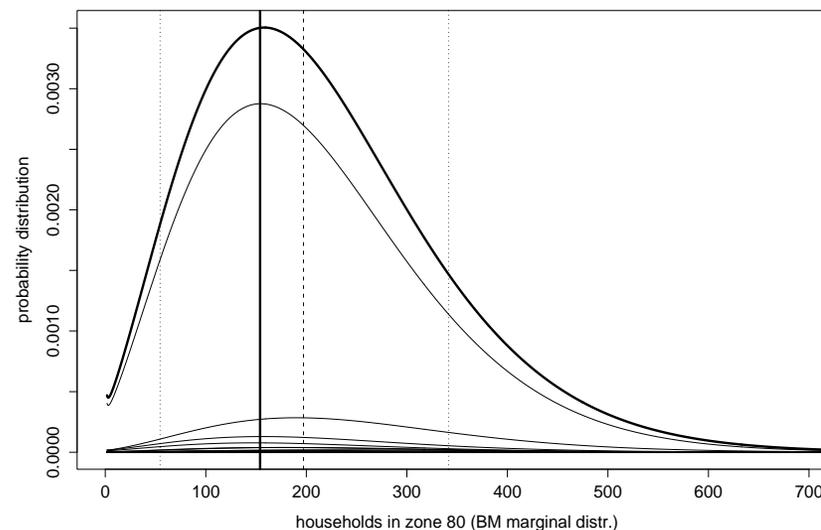
coverage

Results

Multiple runs



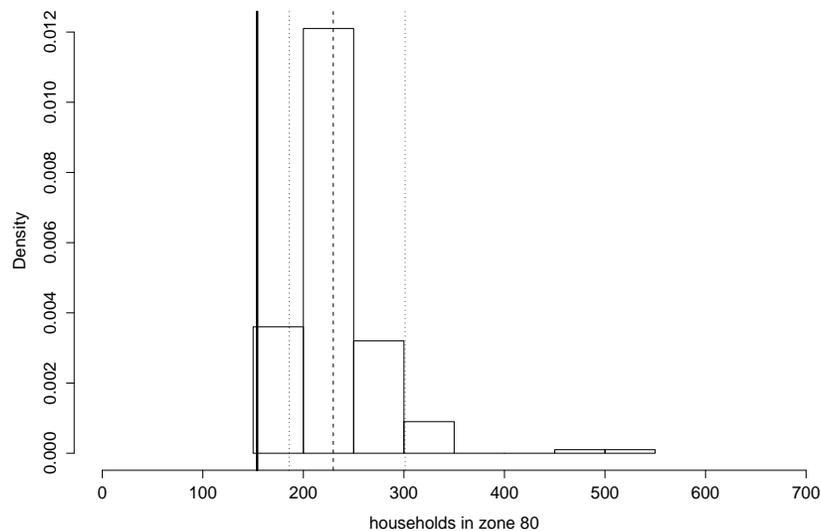
Bayesian melding



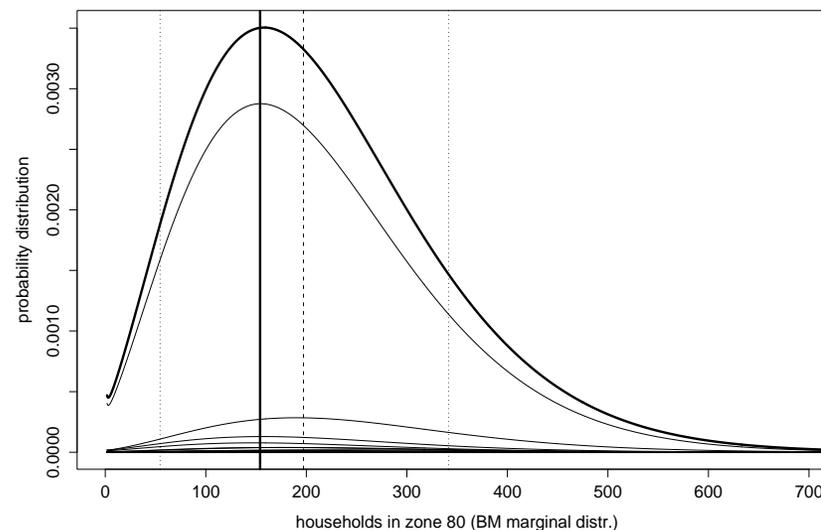
method	missed cases	coverage
multiple runs	163	0.39

Results

Multiple runs



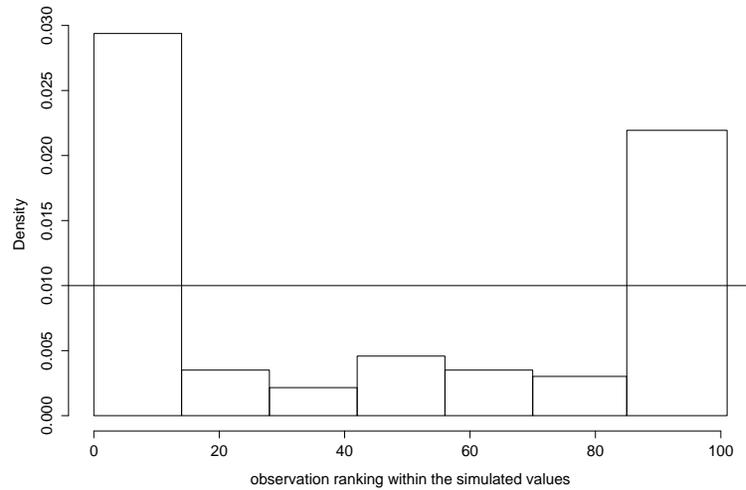
Bayesian melding



method	missed cases	coverage
multiple runs	163	0.39
Bayesian melding	31	0.88

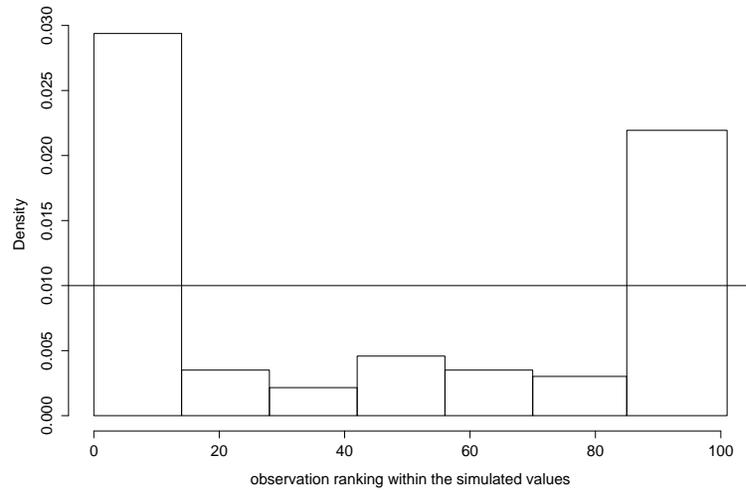
Verification rank histogram

Multiple runs

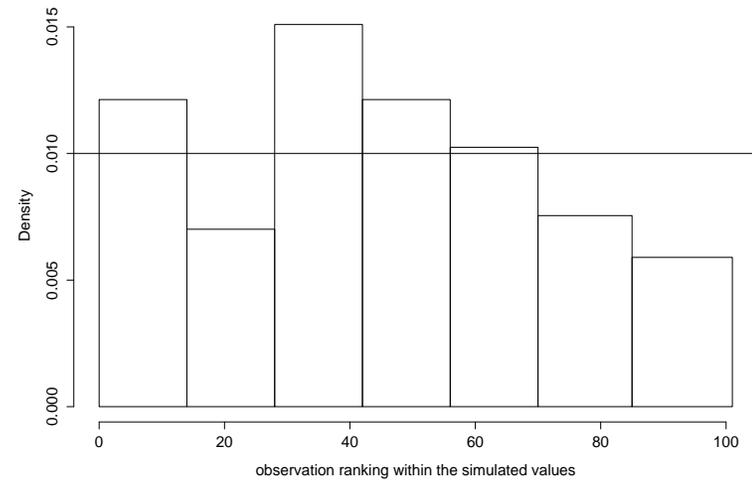


Verification rank histogram

Multiple runs

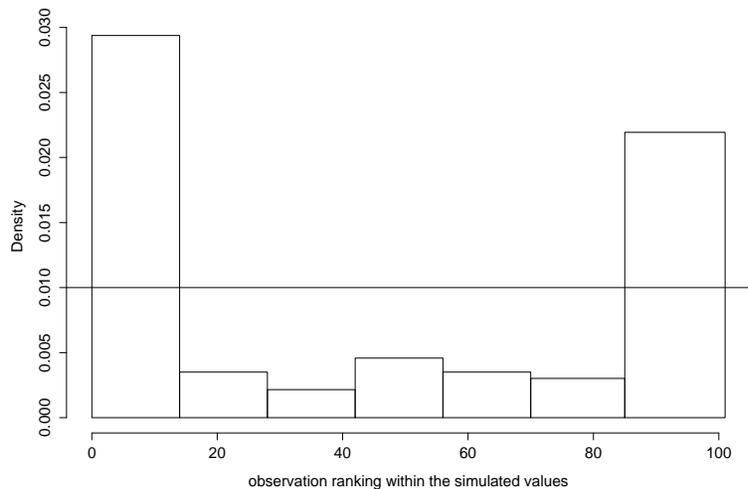


Bayesian melding

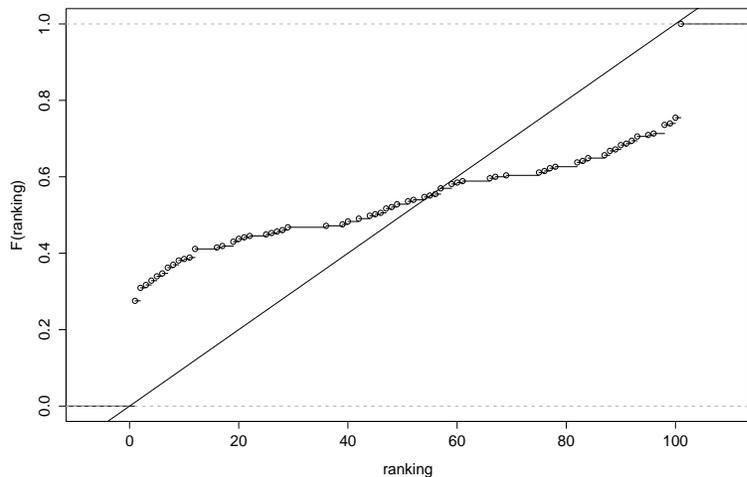
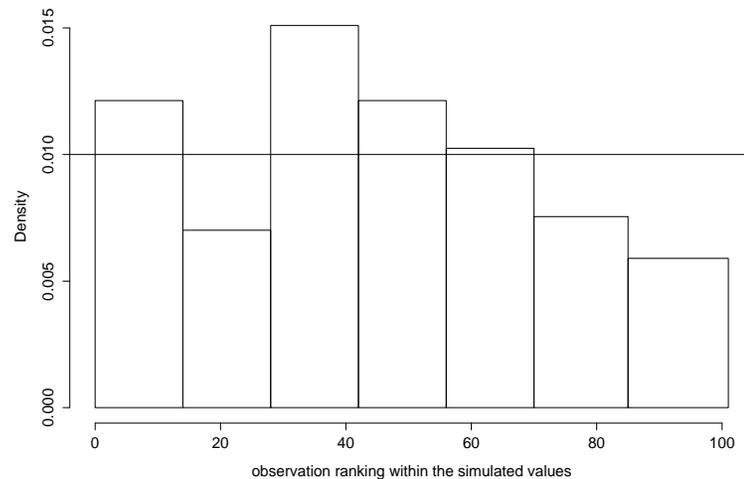


Verification rank histogram

Multiple runs

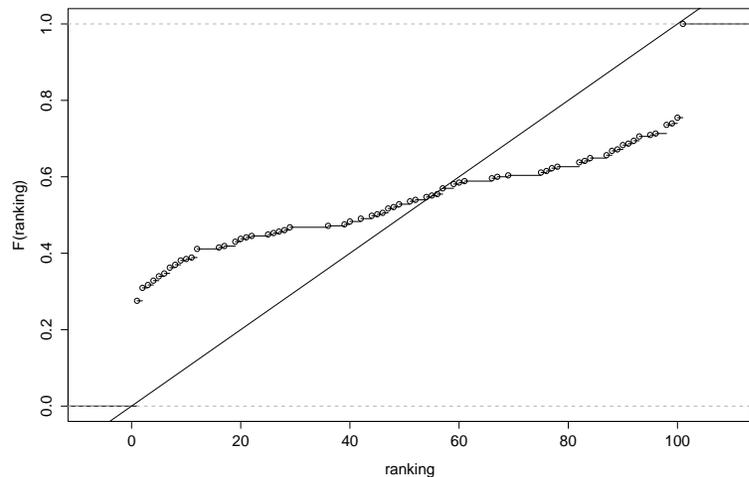
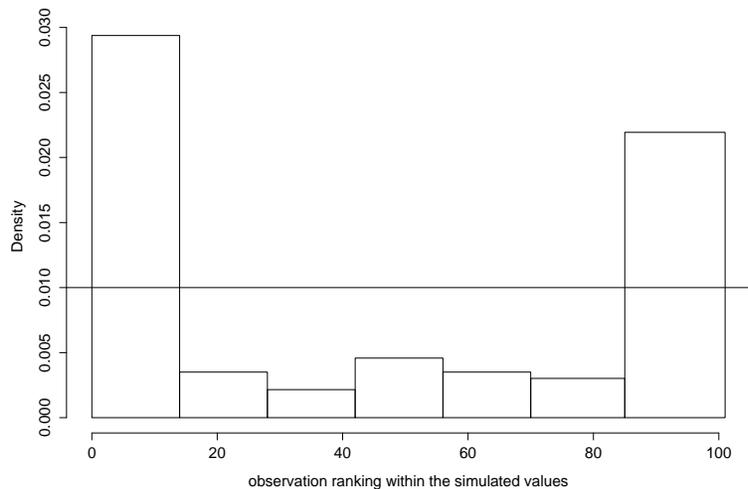


Bayesian melding

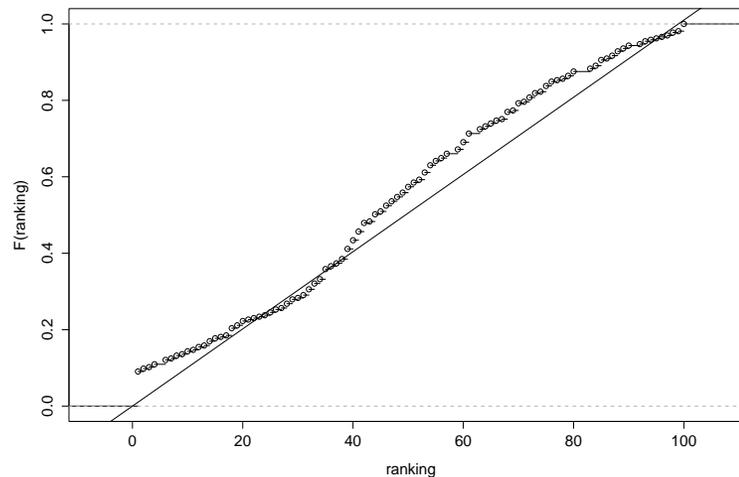
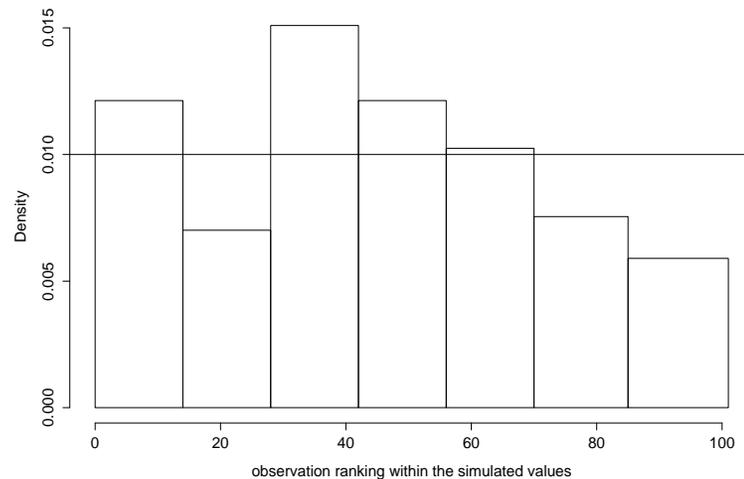


Verification rank histogram

Multiple runs



Bayesian melding



Simulation size

simulation size	100 × 2		1000 × 3	
method	missed cases	coverage	missed cases	coverage

Simulation size

simulation size	100 × 2		1000 × 3	
method	missed cases	coverage	missed cases	coverage
Bayesian melding	31	0.88		

Simulation size

simulation size	100 × 2		1000 × 3	
method	missed cases	coverage	missed cases	coverage
Bayesian melding	31	0.88	29	0.89

Simulation size

simulation size	100 × 2		1000 × 3	
method	missed cases	coverage	missed cases	coverage
Bayesian melding	31	0.88	29	0.89
multiple runs	163	0.39		

Simulation size

simulation size	100 × 2		1000 × 3	
method	missed cases	coverage	missed cases	coverage
Bayesian melding	31	0.88	29	0.89
multiple runs	163	0.39	165	0.38

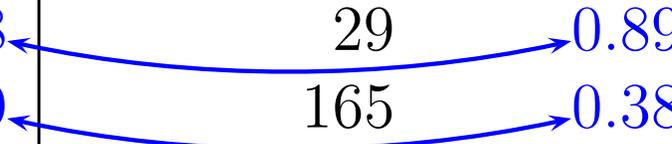
Simulation size

simulation size	100 × 2		1000 × 3	
method	missed cases	coverage	missed cases	coverage
Bayesian melding	31	0.88	29	0.89
multiple runs	163	0.39	165	0.38



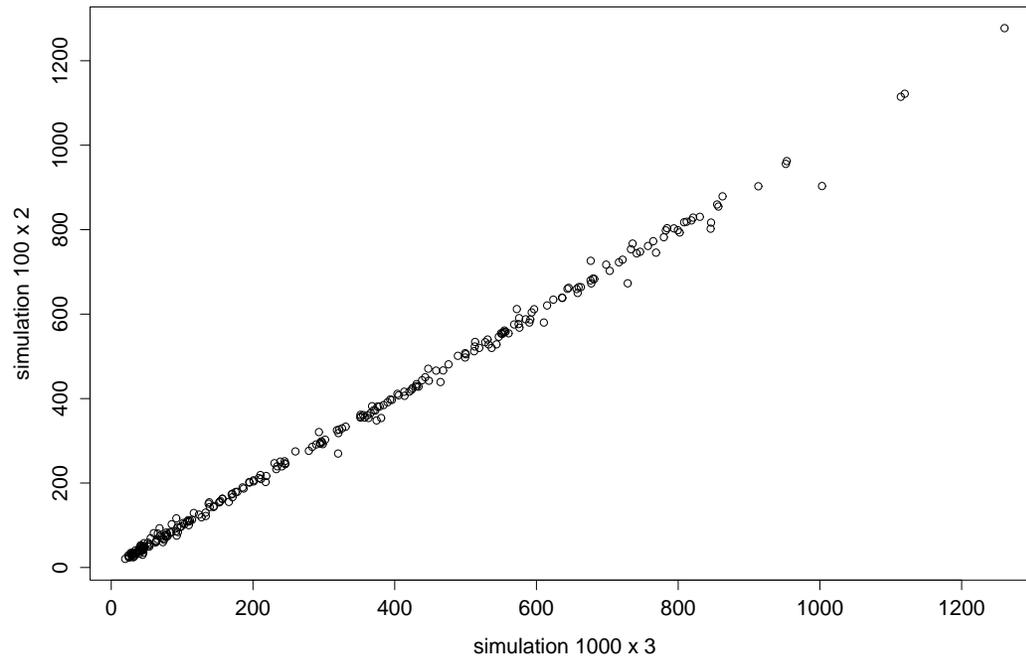
Simulation size

simulation size	100 × 2		1000 × 3	
method	missed cases	coverage	missed cases	coverage
Bayesian melding	31	0.88	29	0.89
multiple runs	163	0.39	165	0.38



Simulation size

simulation size	100 × 2		1000 × 3	
method	missed cases	coverage	missed cases	coverage
Bayesian melding	31	0.88	29	0.89
multiple runs	163	0.39	165	0.38



Summary

- Goal is to assess uncertainty in the output from urban simulation models.

Summary

- Goal is to assess uncertainty in the output from urban simulation models.
- Bayesian melding extended for application to a stochastic simulation model.

Summary

- Goal is to assess uncertainty in the output from urban simulation models.
- Bayesian melding extended for application to a stochastic simulation model.
- Experiment on Eugene, OR, 1980-2000:

Summary

- Goal is to assess uncertainty in the output from urban simulation models.
- Bayesian melding extended for application to a stochastic simulation model.
- Experiment on Eugene, OR, 1980-2000:
 - ◆ Simple multiple runs underestimated uncertainty.

Summary

- Goal is to assess uncertainty in the output from urban simulation models.
- Bayesian melding extended for application to a stochastic simulation model.
- Experiment on Eugene, OR, 1980-2000:
 - ◆ Simple multiple runs underestimated uncertainty.
 - ◆ Bayesian melding provided well calibrated results.