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Geostatistics (1)

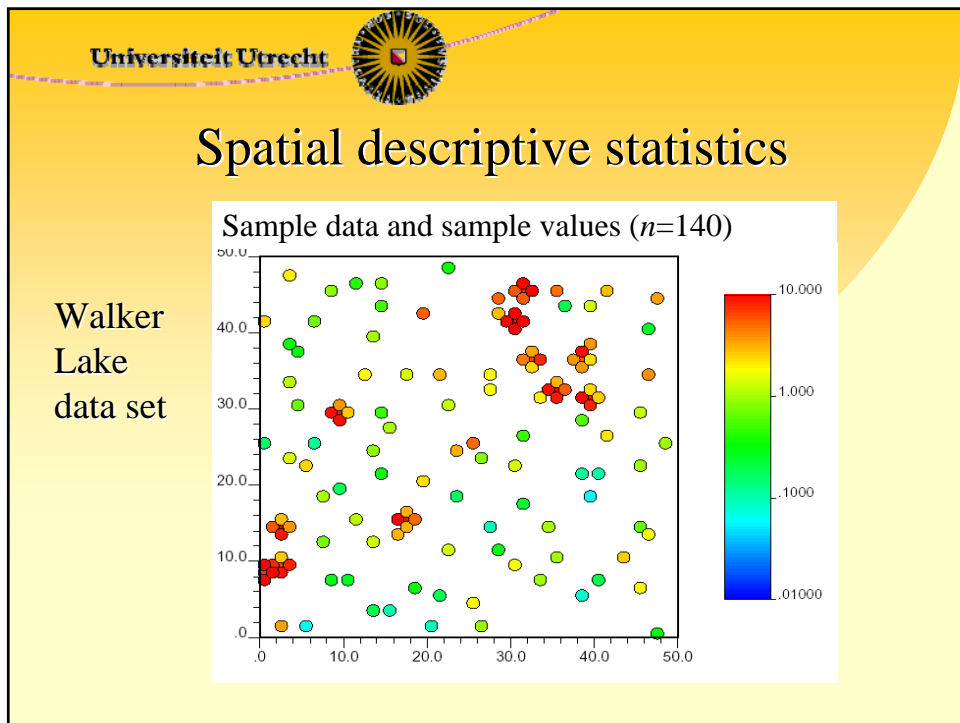
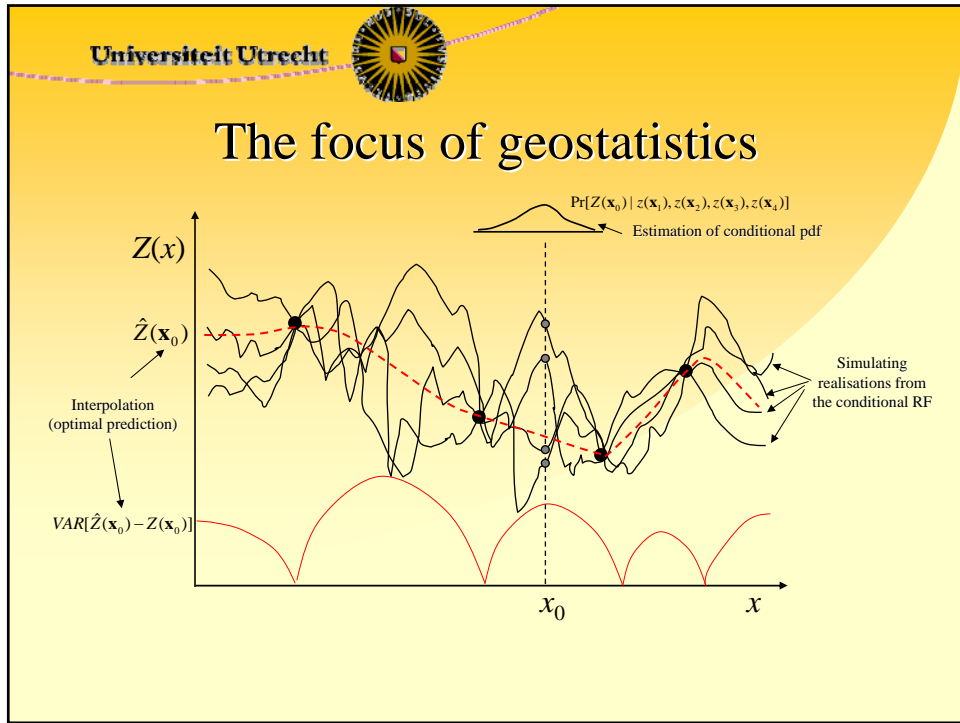
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Faculty of Geosciences


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The focus of geostatistics

Diagram illustrating the focus of geostatistics: a central point \mathbf{x}_0 (with a question mark above it) is surrounded by four other points $\mathbf{x}_1, \mathbf{x}_2, \mathbf{x}_3, \mathbf{x}_4$. Each point is labeled with its corresponding z value: z_1, z_2, z_3, z_4 .

- Interpolation: prediction $\hat{Z}(\mathbf{x}_0)$ and prediction variance $\text{VAR}[\hat{Z}(\mathbf{x}_0) - Z(\mathbf{x}_0)]$
- Estimation of the conditional probability: $\text{Pr}[Z(\mathbf{x}_0) | z(\mathbf{x}_1), z(\mathbf{x}_2), z(\mathbf{x}_3), z(\mathbf{x}_4)]$
- Simulation of realisations of the conditional RF $Z(\mathbf{x} | z(\mathbf{x}_1), z(\mathbf{x}_2), z(\mathbf{x}_3), z(\mathbf{x}_4))$



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Spatial descriptive statistics

Polygon declustering

$$m_z = \sum_{i=1}^n w_i z_i$$

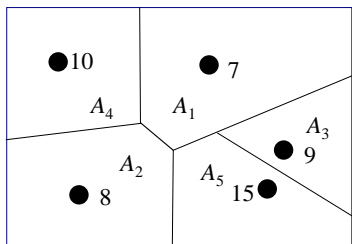
$$\sigma_z^2 = \sum_{i=1}^n w_i (z_i - m_z)^2$$

$$w_1 = \frac{A_1}{A_1 + A_2 + A_3 + A_4 + A_5}$$

$$w_2 = \frac{A_2}{A_1 + A_2 + A_3 + A_4 + A_5}$$


etc.

$A_1 = 0.30$
 $A_2 = 0.25$
 $A_3 = 0.10$
 $A_4 = 0.20$
 $A_5 = 0.15$



$$m_z = 0.3 \cdot 7 + 0.25 \cdot 8 + 0.10 \cdot 9 + 0.20 \cdot 10 + 0.15 \cdot 15 = 9.25$$

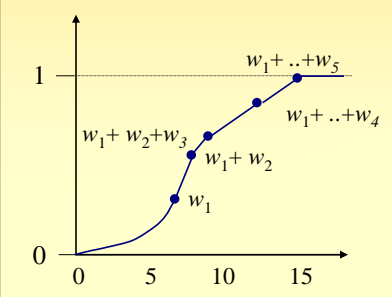
$$s_z^2 = 0.3 \cdot (-2.25)^2 + 0.25 \cdot (-1.25)^2 + 0.10 \cdot (-0.25)^2 + 0.20 \cdot (0.75)^2 + 0.15 \cdot (5.75)^2 = 6.99$$

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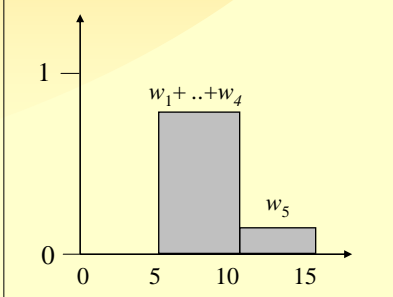
Spatial descriptive statistics

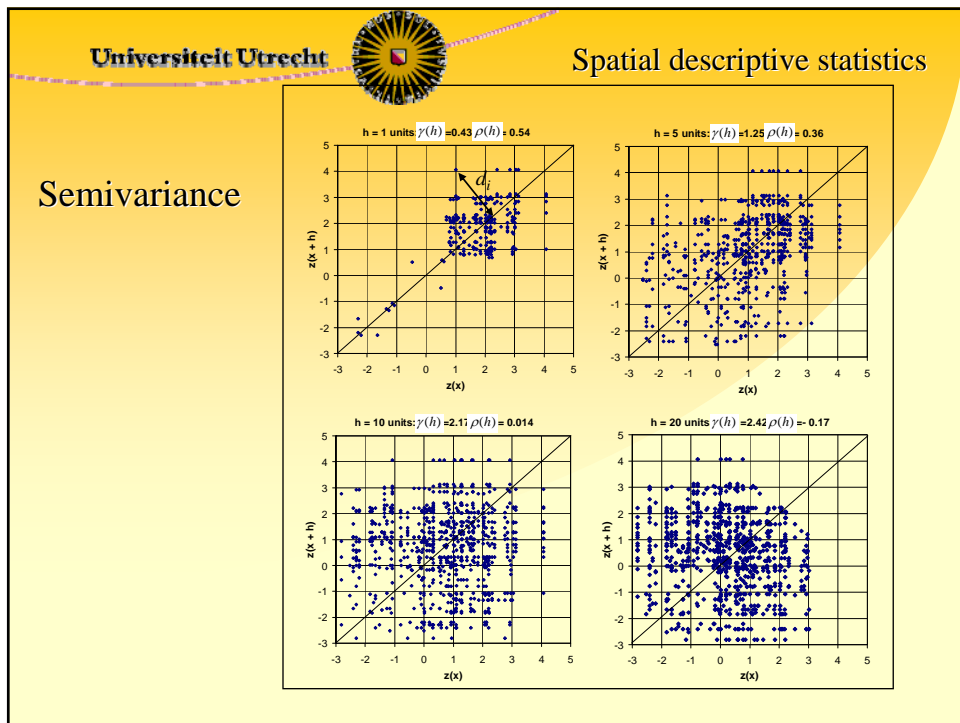
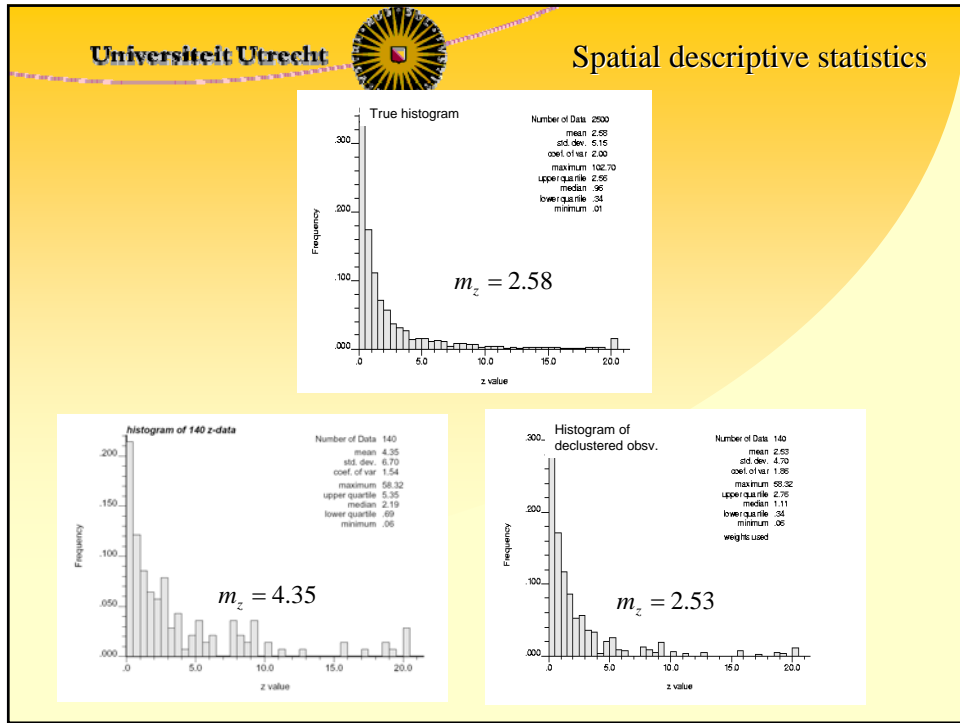
Declustered histogram and cumulative frequency distribution

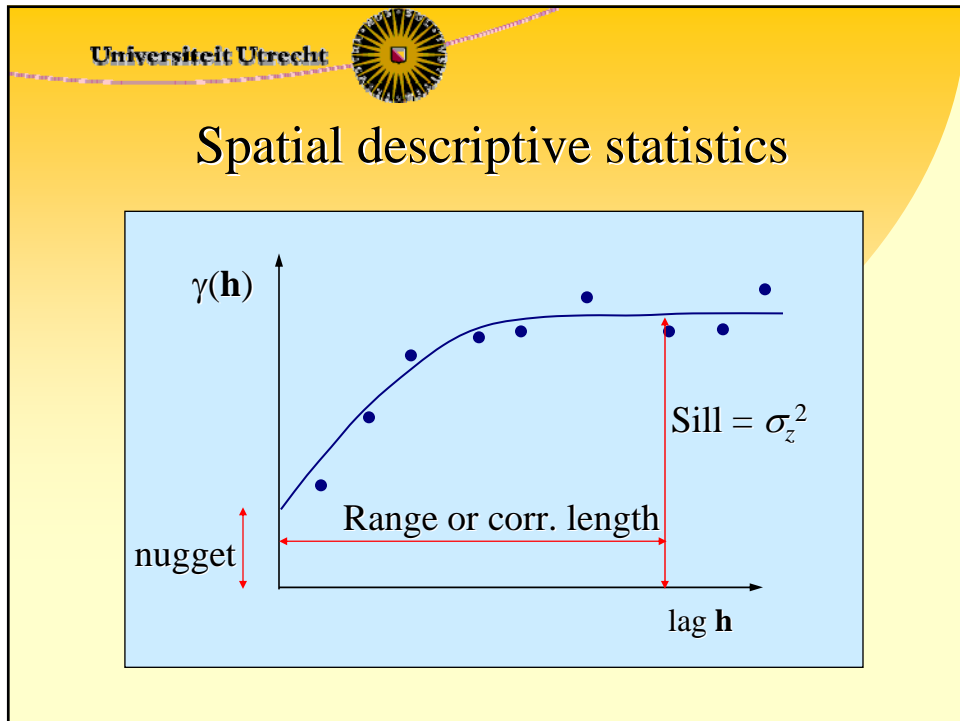
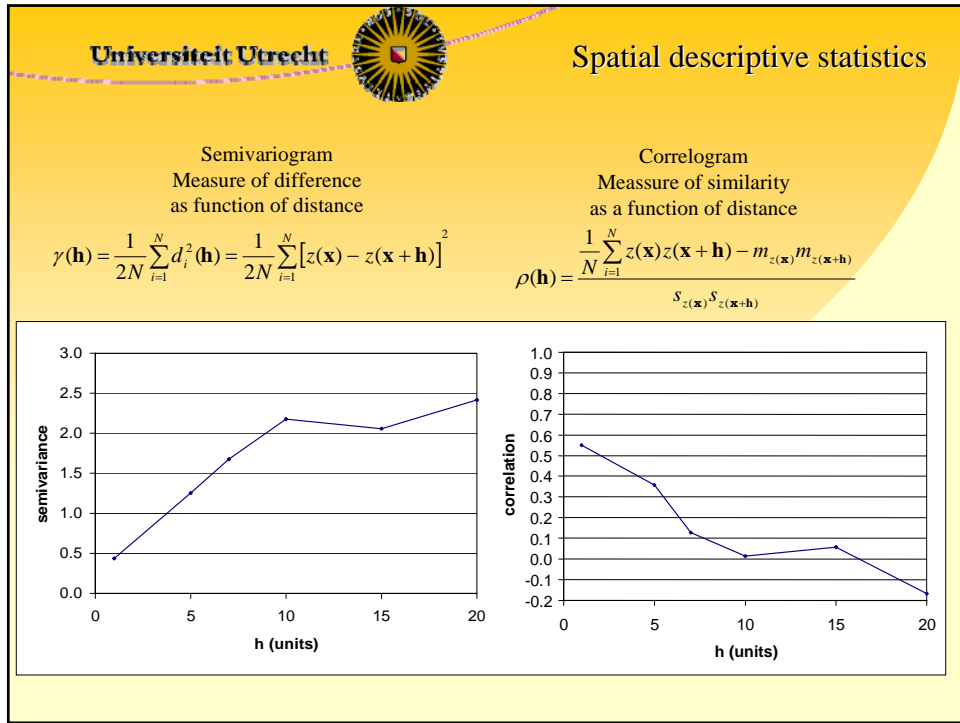
Declustered cum. Freq. Distr.



Declustered histogram









Interpolation by Kriging

Simple Kriging

Wide sense stationary RF:

$$\mu_z(\mathbf{x}) = \mu_z \text{ (constant)}$$

Variance σ_z^2 is constant and finite

$$\text{Cov}(Z(\mathbf{x}_1), Z(\mathbf{x}_2)) = C_Z(\mathbf{x}_1 - \mathbf{x}_2) = C_Z(\mathbf{h})$$

Simple Kriging if:

- RF is wide sense stationary, and
- mean μ_z is known.



Interpolation by Kriging

Simple Kriging

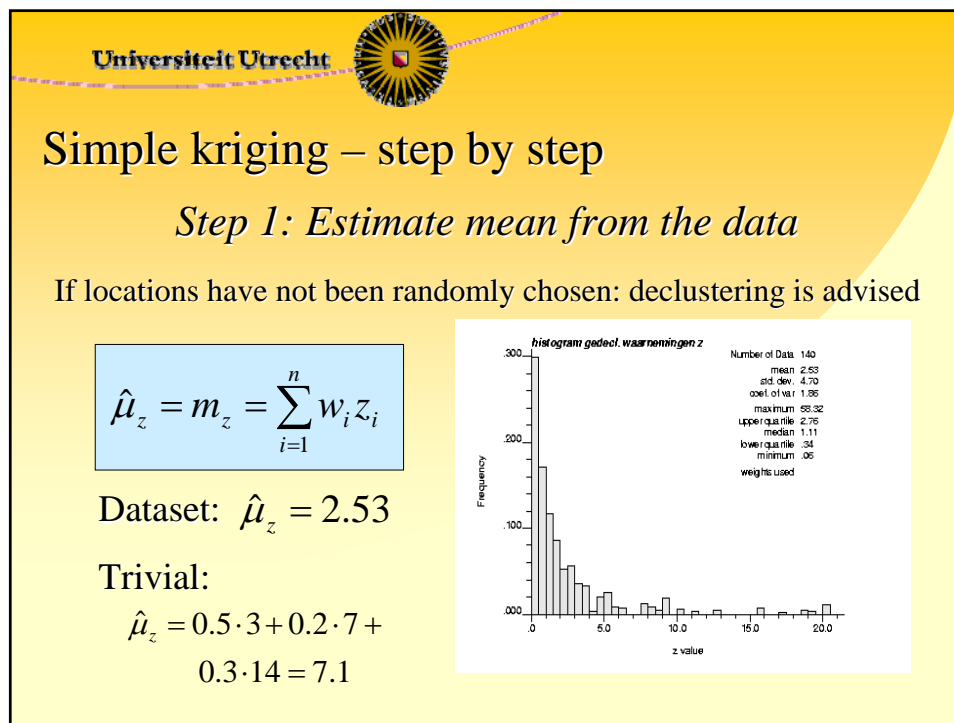
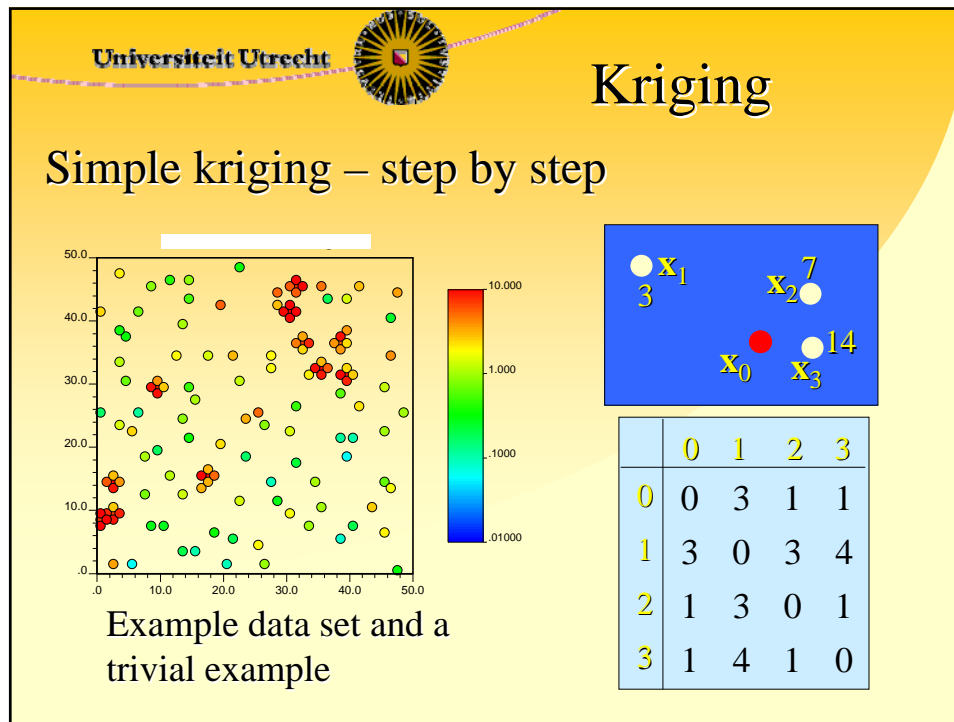
Linear Predictor:

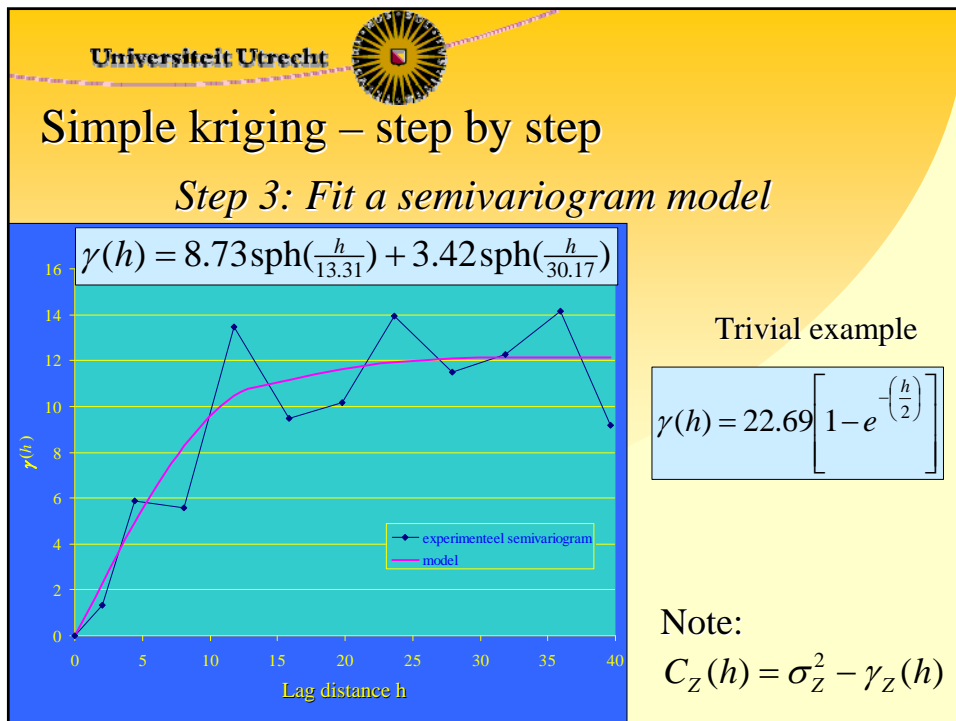
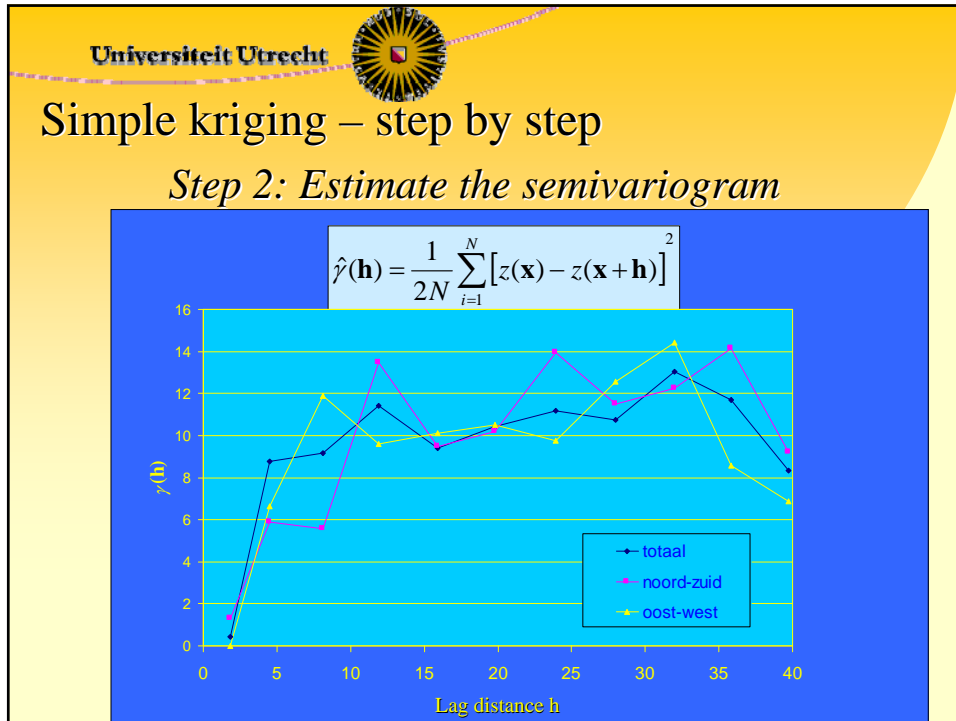
$$\hat{Z}(\mathbf{x}_0) = \mu_z + \sum_{i=1}^n \lambda_i (Z_i - \mu_z)$$

Unbiased prediction means: $E[\hat{Z}(\mathbf{x}_0)] = E[Z(\mathbf{x}_0)]$

Simple kriging predictor is by definition unbiased!

Find the λ_i such that the error variance: $\text{VAR}[\hat{Z}(\mathbf{x}_0) - Z(\mathbf{x}_0)]$ is minimal!



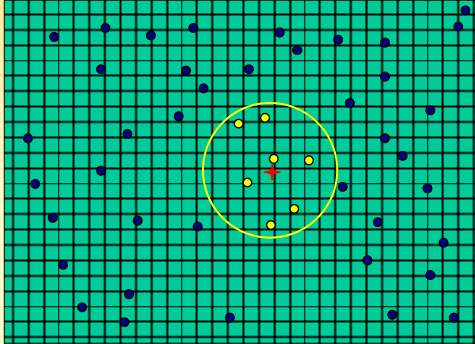


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Simple kriging – step by step

Step 4: Select observations within a search radius

Based on semivariogram range



Note: this step and all the next ones are repeated for every prediction location

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Simple kriging – step by step

Step 5: Solve the kriging equations for λ_i

$$\sum_{j=1}^n \lambda_j C(\mathbf{x}_i - \mathbf{x}_j) = C(\mathbf{x}_i - \mathbf{x}_0) \quad i = 1, \dots, n$$

with $C(\mathbf{x}_i - \mathbf{x}_j) = \sigma_z^2 - \gamma(\mathbf{x}_i - \mathbf{x}_j)$

Trivial:

$$\lambda_1 C(\mathbf{x}_1 - \mathbf{x}_1) + \lambda_2 C(\mathbf{x}_1 - \mathbf{x}_2) + \lambda_3 C(\mathbf{x}_1 - \mathbf{x}_3) = C(\mathbf{x}_1 - \mathbf{x}_0)$$

$$\lambda_1 C(\mathbf{x}_2 - \mathbf{x}_1) + \lambda_2 C(\mathbf{x}_2 - \mathbf{x}_2) + \lambda_3 C(\mathbf{x}_2 - \mathbf{x}_3) = C(\mathbf{x}_2 - \mathbf{x}_0)$$

$$\lambda_1 C(\mathbf{x}_3 - \mathbf{x}_1) + \lambda_2 C(\mathbf{x}_3 - \mathbf{x}_2) + \lambda_3 C(\mathbf{x}_3 - \mathbf{x}_3) = C(\mathbf{x}_3 - \mathbf{x}_0)$$

Met $C(\mathbf{x}_i - \mathbf{x}_j) = 22.69e^{-\frac{|\mathbf{x}_i - \mathbf{x}_j|}{2}}$

	0	1	2	3
0	0	3	1	1
1	3	0	3	4
2	1	3	0	1
3	1	4	1	0



Simple kriging – step by step

Step 5: Solve the kriging equation for λ_i

Trivial:

$$22.69\lambda_1 + 5.063\lambda_2 + 3.071\lambda_3 = 5.063$$

$$5.063\lambda_1 + 22.69\lambda_2 + 13.76\lambda_3 = 13.76$$

$$3.071\lambda_1 + 13.76\lambda_2 + 22.69\lambda_3 = 13.76$$

Solution:

$$\lambda_1 = 0.0924 \quad \lambda_2 = 0.357 \quad \lambda_3 = 0.378$$



Simple kriging – step by step

Step 6: Kriging prediction

$$\hat{Z}(\mathbf{x}) = \mu_z + \sum_{i=1}^n \lambda_i [Z(\mathbf{x}_i) - \mu_z]$$

Trivial:

$$\hat{Z}(\mathbf{x}) = 7.1 + 0.0924 \cdot (-4.1) + 0.357 \cdot (-0.1) + 0.378 \cdot 6.9 = 9.29$$



Simple kriging – step by step

Step 7: Kriging variance

$$\text{var}[\hat{Z}(\mathbf{x}_0) - Z(\mathbf{x}_0)] = \sigma_z^2 - \sum_{i=1}^n \lambda_i C(\mathbf{x}_i - \mathbf{x}_0)$$

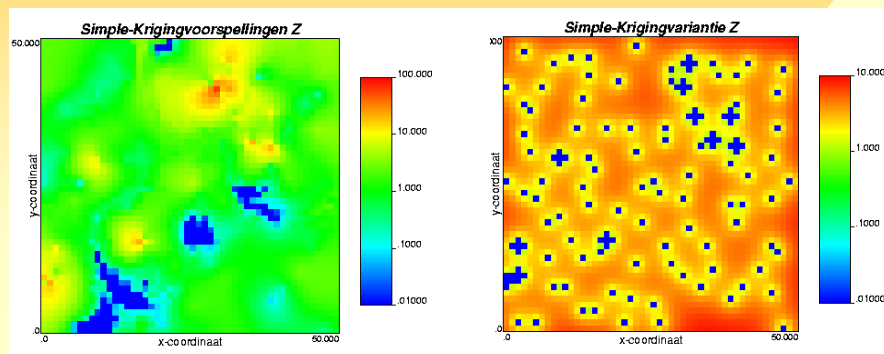
Trivial:

$$\hat{Z}(\mathbf{x}_0) - Z(\mathbf{x}_0) = 2.003 + 0.321 \cdot 13.10 + 0.318 \cdot 13.10 = 15.11$$

$$\Delta \text{var}[\hat{Z}(\mathbf{x}_0) - Z(\mathbf{x}_0)] =$$



Kriging prediction and kriging variance





Ordinary kriging

Intrinsic random function:

- Constant mean $\mu_z(\mathbf{x}) = \mu_z$
- Semivariogram a function of separation only

$$\gamma(Z(\mathbf{x}_1), Z(\mathbf{x}_2)) = \gamma(\mathbf{x}_1 - \mathbf{x}_2) = \gamma(\mathbf{h})$$



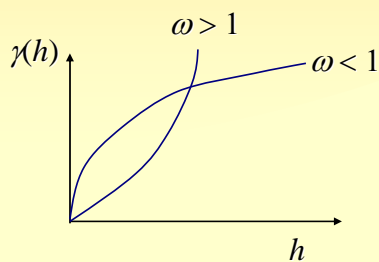
Ordinary kriging

Wide sense stationary RF: semivariogram has sill: $C_z(h) = \sigma_z^2 - \gamma_z(h)$

Intrinsic RF: semivariogram does not have to have a sill

Example: power semivariogram

$$\gamma(h) = ch^\omega \quad 0 \leq \omega < 2$$



- Wide sense stationary RF is also intrinsic, but not vice versa;
- An intrinsic RF is also wide sense stationary if the semivariogram has a sill.



Ordinary kriging

Ordinary Kriging is applied if:

- an intrinsic RF is assumed, or
- a wide sense stationary RF is assumed, but the mean μ_Z is not known



Ordinary kriging: step by step

Step 1: Estimate the semivariogram

Step 2: Fit a semivariogram model

$$\gamma(h) = 8.73 \text{sph}\left(\frac{h}{13.31}\right) + 3.42 \text{sph}\left(\frac{h}{30.17}\right)$$

For trivia:

$$\gamma(h) = 22.69 \left[1 - e^{-\left(\frac{h}{2}\right)} \right]$$

*Step 3: Select observations with search radius**

*This and next steps repeated for each prediction location



Ordinary kriging: step by step

Step 4: Solve kriging system

$$\begin{cases} \sum_{j=1}^n \lambda_j \gamma(\mathbf{x}_i - \mathbf{x}_j) + \nu = \gamma(\mathbf{x}_i - \mathbf{x}_0) & i = 1, \dots, n \\ \sum_{i=1}^n \lambda_i = 1 \end{cases}$$

Trivial:

$$\begin{aligned} \lambda_1 \gamma(\mathbf{x}_1 - \mathbf{x}_1) + \lambda_2 \gamma(\mathbf{x}_1 - \mathbf{x}_2) + \lambda_3 \gamma(\mathbf{x}_1 - \mathbf{x}_3) + \nu &= \gamma(\mathbf{x}_1 - \mathbf{x}_0) \\ \lambda_1 \gamma(\mathbf{x}_2 - \mathbf{x}_1) + \lambda_2 \gamma(\mathbf{x}_2 - \mathbf{x}_2) + \lambda_3 \gamma(\mathbf{x}_2 - \mathbf{x}_3) + \nu &= \gamma(\mathbf{x}_2 - \mathbf{x}_0) \\ \lambda_1 \gamma(\mathbf{x}_3 - \mathbf{x}_1) + \lambda_2 \gamma(\mathbf{x}_3 - \mathbf{x}_2) + \lambda_3 \gamma(\mathbf{x}_3 - \mathbf{x}_3) + \nu &= \gamma(\mathbf{x}_3 - \mathbf{x}_0) \\ \lambda_1 + \lambda_2 + \lambda_3 &= 1 \end{aligned}$$

Met $\gamma(\mathbf{x}_i - \mathbf{x}_j) = 22.69(1 - e^{-\frac{|\mathbf{x}_i - \mathbf{x}_j|}{2}})$

	0	1	2	3
0	0	3	1	1
1	3	0	3	4
2	1	3	0	1
3	1	4	1	0



Ordinary kriging: step by step

Step 4: Solve the kriging system

Trivial:

$$\begin{aligned} 17.627\lambda_2 + 19.619\lambda_3 + \nu &= 17.628 \\ 16.627\lambda_1 + 8.930\lambda_3 + \nu &= 8.930 \\ 19.619\lambda_1 + 8.930\lambda_2 + \nu &= 8.930 \\ \lambda_1 + \lambda_2 + \lambda_3 &= 1 \end{aligned}$$

Solution:

$$\lambda_1 = 0.172 \quad \lambda_2 = 0.381 \quad \lambda_3 = 0.447 \quad \nu = 2.147$$



Ordinary kriging: step by step

Step 5: Kriging prediction

$$\hat{Z}(\mathbf{x}_0) = \sum_{i=1}^n \lambda_i Z(\mathbf{x}_i)$$

Trivial:

$$\hat{Z}(\mathbf{x}_0) = 0.172 \cdot 3 + 0.381 \cdot 7 + 0.447 \cdot 14 = 9.44$$



Ordinary kriging: step by step

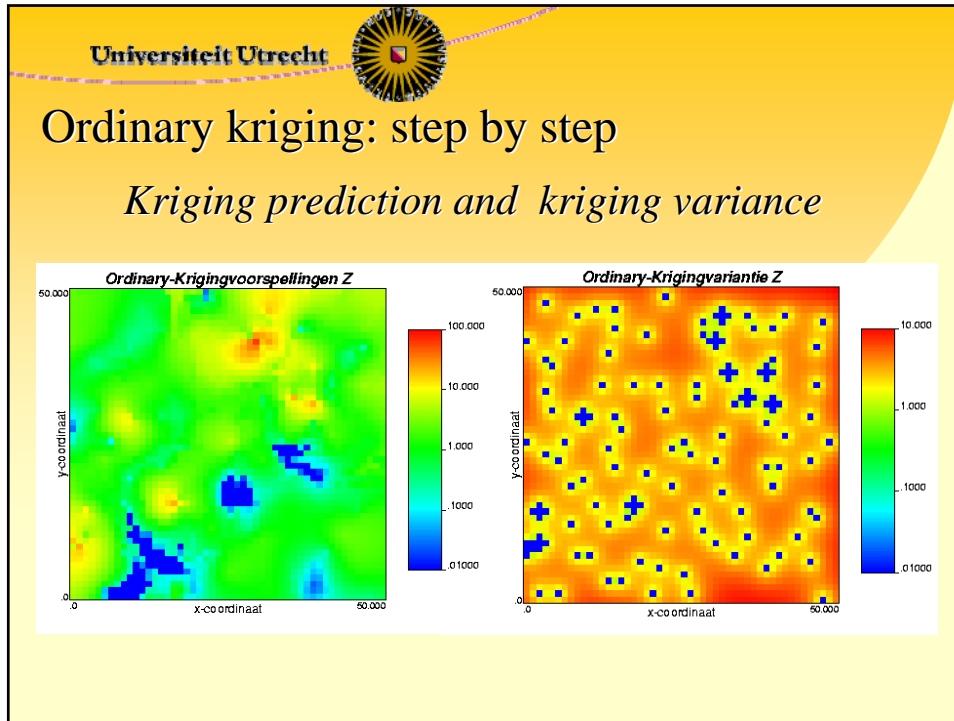
Step 6: Kriging variance

$$\text{var}[\hat{Z}(\mathbf{x}_0) - Z(\mathbf{x}_0)] = \sum_{i=1}^n \lambda_i \gamma(\mathbf{x}_i - \mathbf{x}_0) + \nu$$

Trivial:

$$\hat{Z}(\mathbf{x}_0) - Z(\mathbf{x}_0) = 0.172 \cdot 14.25 + 0.381 \cdot 8.030 + 0.447 \cdot 8.030 + 5.14 = 15.21$$

$$\Delta \text{var}[\hat{Z}(\mathbf{x}_0) - Z(\mathbf{x}_0)] =$$



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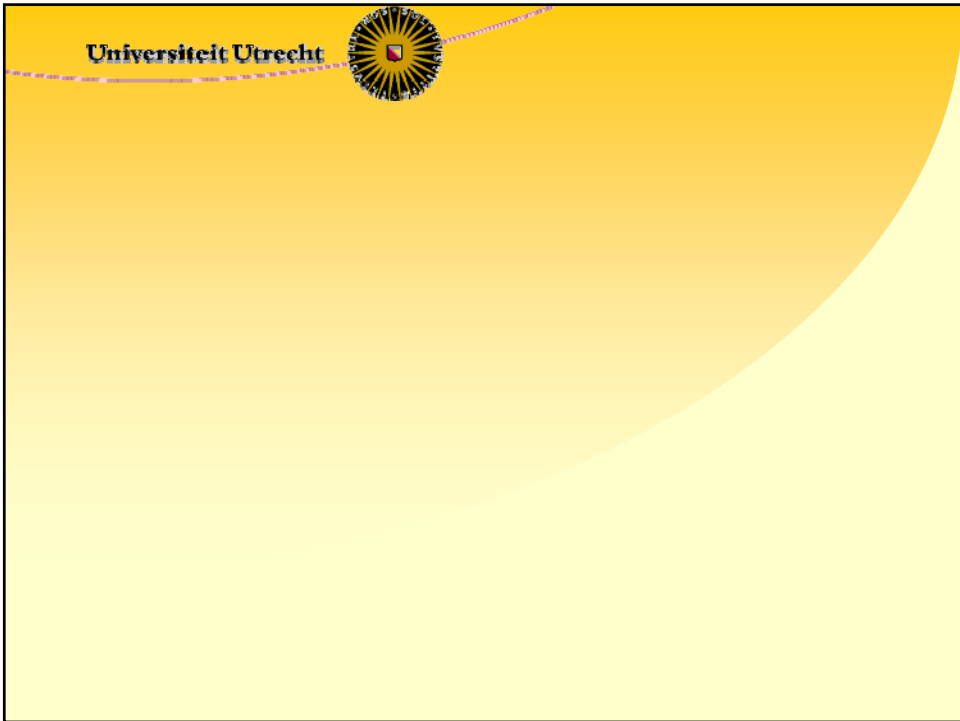
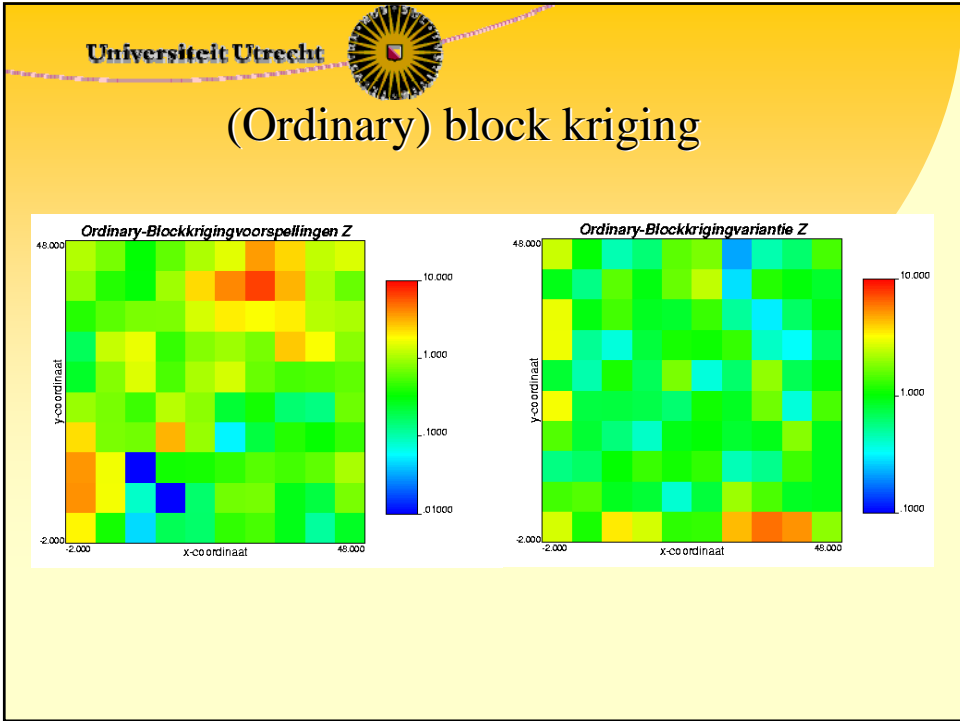
(Ordinary) block kriging


$$\hat{Z}_B = \sum_{i=1}^n \lambda_i Z(\mathbf{x}_i)$$

$$\begin{cases} \sum_{j=1}^n \lambda_j \gamma(\mathbf{x}_i - \mathbf{x}_j) + \nu = \gamma(\mathbf{x}_i, B) & i=1, \dots, n \\ \sum_{i=1}^n \lambda_i = 1 \end{cases}$$

$$\text{var}[\hat{Z}_B - Z_B] = \sum_{j=1}^n \lambda_j \gamma(\mathbf{x}_i, B) + \nu - \gamma(B, B)$$


Ordinary block kriging can serve as declustering algorithm



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Geostatistics (2)

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Estimating conditional probability

$$\Pr[Z(\mathbf{x}_0) \leq z \mid z(\mathbf{x}_1), \dots, z(\mathbf{x}_n)]$$

Three ways:

- MultiGaussian kriging ←
- Indicator kriging
- Disjunctive kriging



Estimating conditional probability

MultiGaussian kriging

Heavy assumptions:

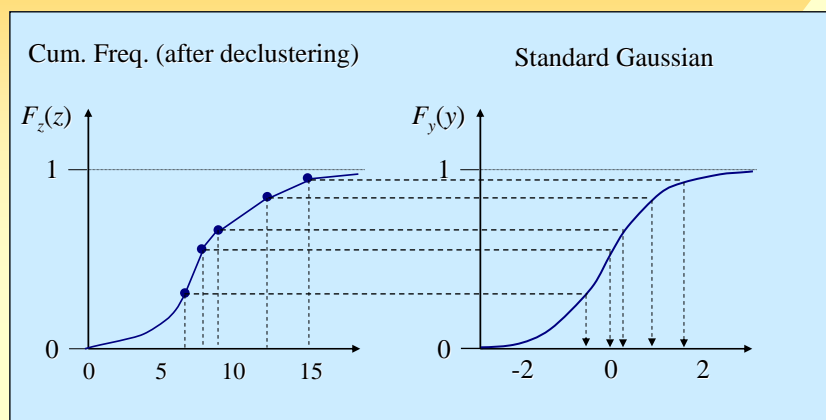
- $Z(\mathbf{x})$ is wide sense stationary
- Any set of values $Z(\mathbf{x}_1), \dots, Z(\mathbf{x}_N)$ (or their transforms) are jointly Gaussian distributed.



Conditional probability

MultiGaussian kriging step by step

Step 1: Normal-score transformation of data





MultiGaussian kriging step by step

- 2 Estimate semivariogram of transforms Y
Note: Semivariogram must have a sill!
- 3 Simple kriging Y -values with $\mu_Y = 0$: yields prediction $\hat{Y}(\mathbf{x}_0)$ and kriging-variance $\sigma_Y^2(\mathbf{x}_0)$
- 4 Calculate cumulative probability as:

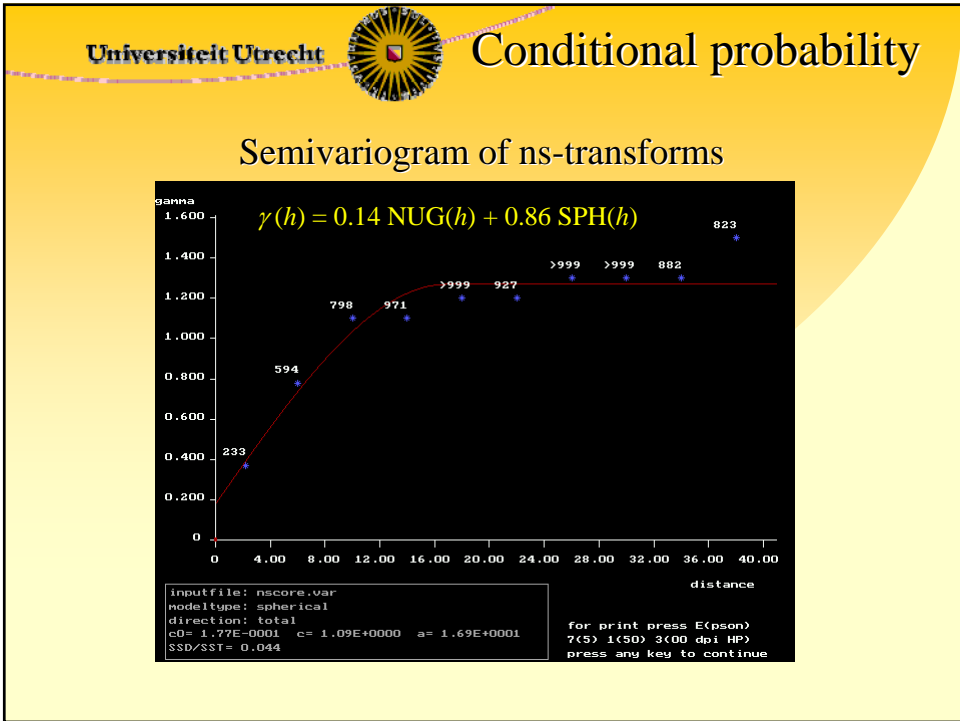
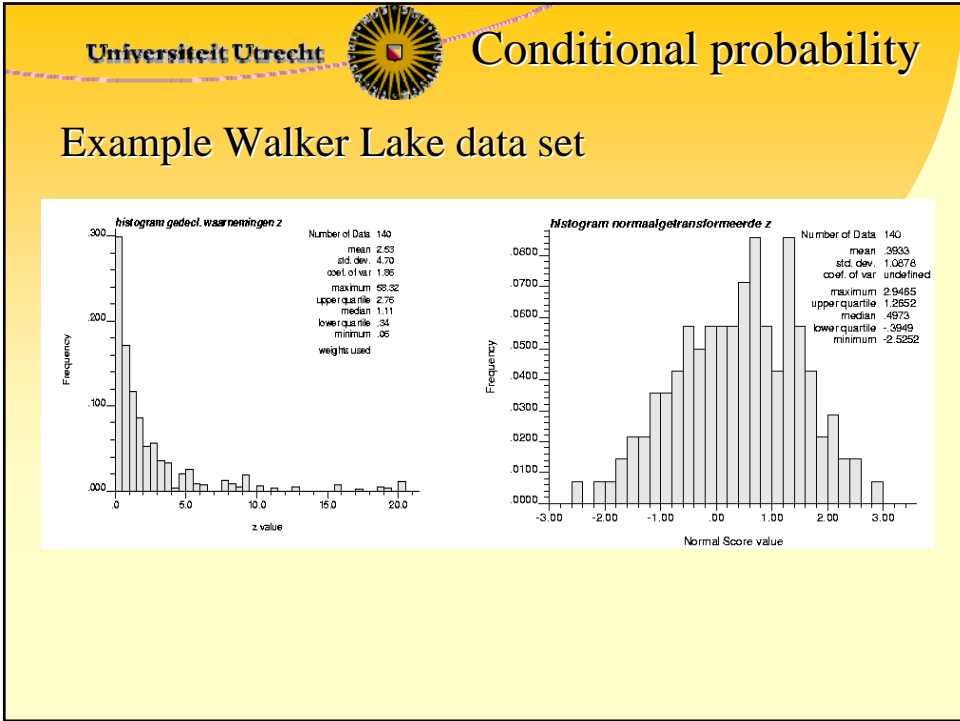
$$\Pr[Z(\mathbf{x}_0) \leq z \mid z(\mathbf{x}_i), i = 1, \dots, n] = \frac{1}{\sqrt{2\pi\sigma_Y^2(\mathbf{x}_0)}} \int_{-\infty}^z \exp\left(\frac{-[y_{ns}(z) - \hat{y}(\mathbf{x}_0)]^2}{\sigma_Y^2(\mathbf{x}_0)}\right)$$

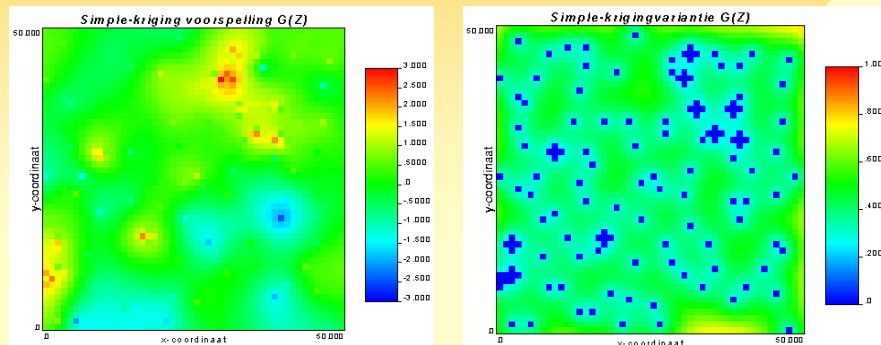


2. De multiGaussian method

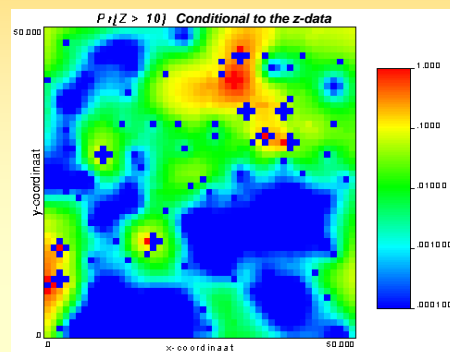
Two additional reasons for taking normal score transforms:

- Stabilisation of variance: better estimates of the semivariogram.
- Values have to be within a given range (e.g. only positive, between 0 en 1).



Simple kriging prediction Y and kriging variance

Example of exceedence probability: $z_c = 10 \rightarrow y_c = G(10) = 1.757$.





Question: How do we obtain $\hat{Z}(\mathbf{x}_0)$
from $\hat{Y}(\mathbf{x}_0)$ and $\sigma_{\hat{Y}}^2(\mathbf{x}_0)$?

Coffee Break

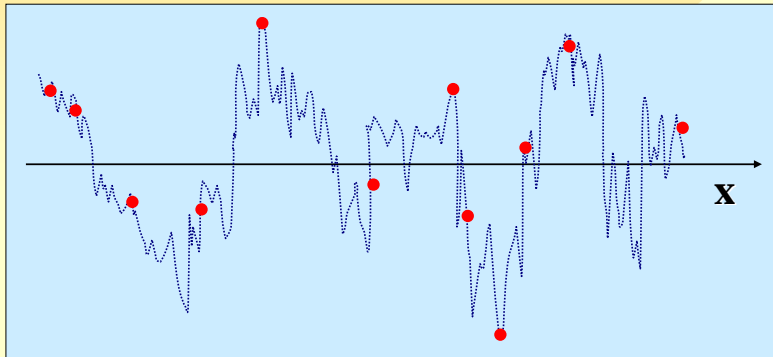


Geostatistical Simulation

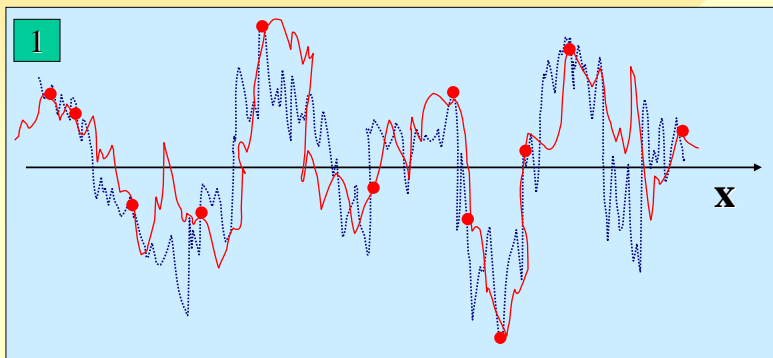
Simulating realisations of a (spatial) random function



Geostatistical Simulation

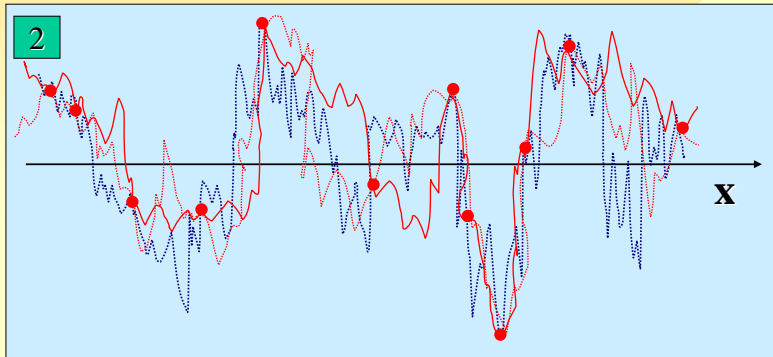


Geostatistical Simulation

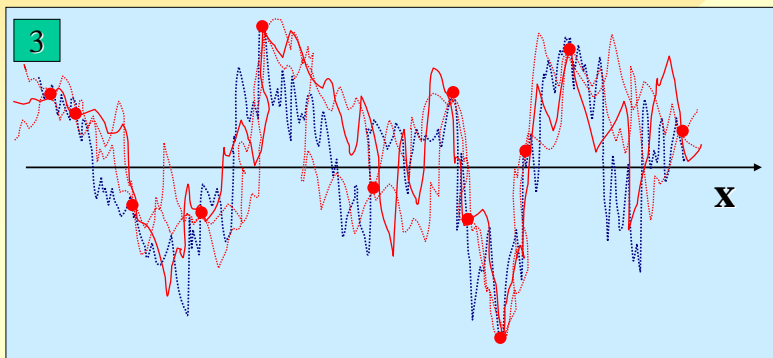




Geostatistical Simulation

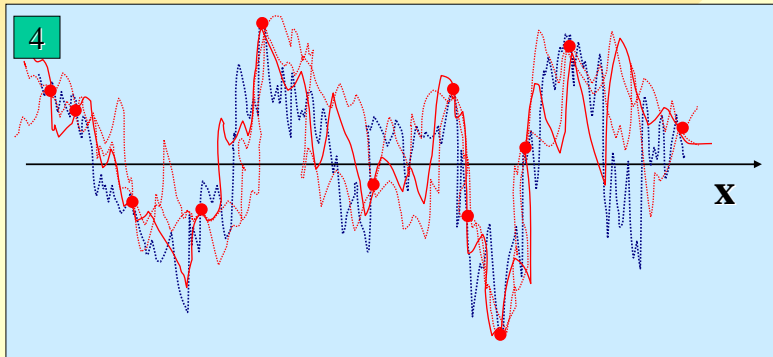


Geostatistical Simulation

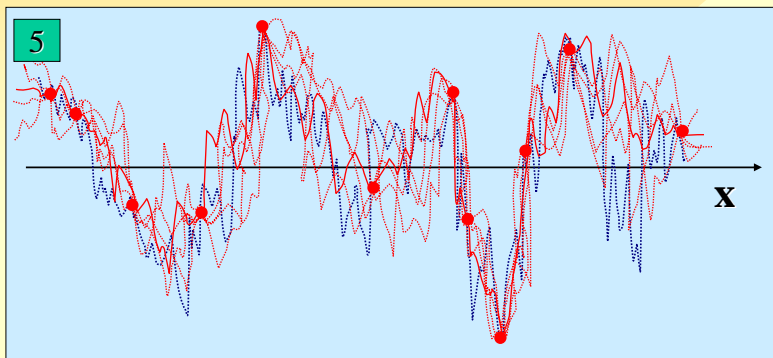




Geostatistical Simulation

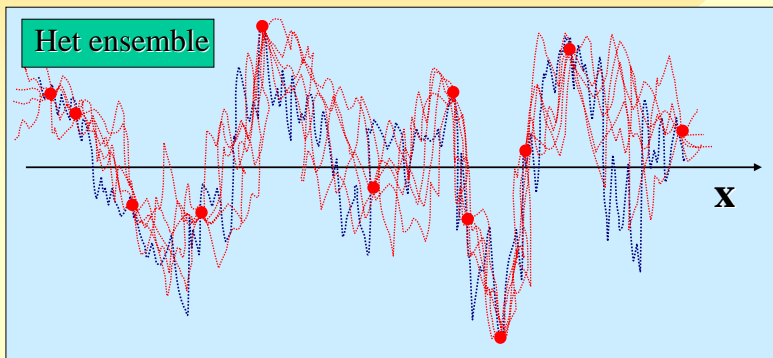


Geostatistical Simulation

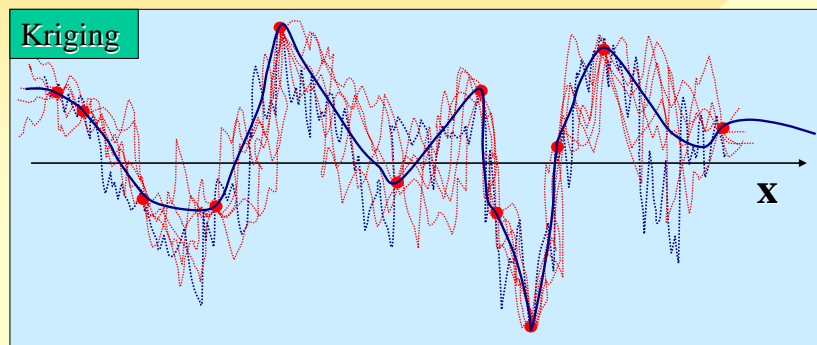


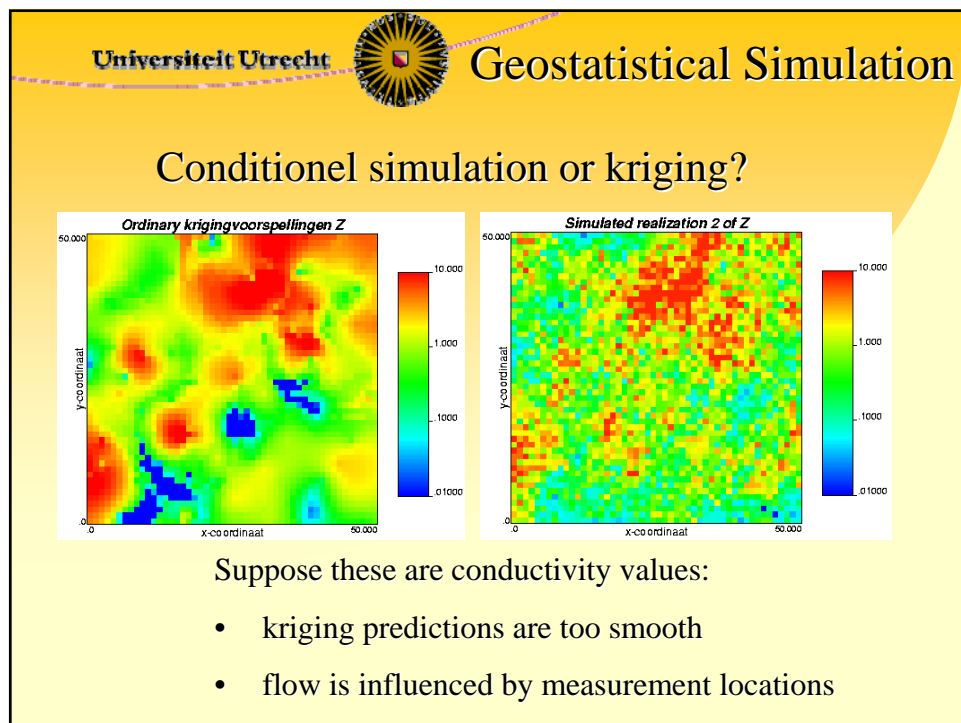
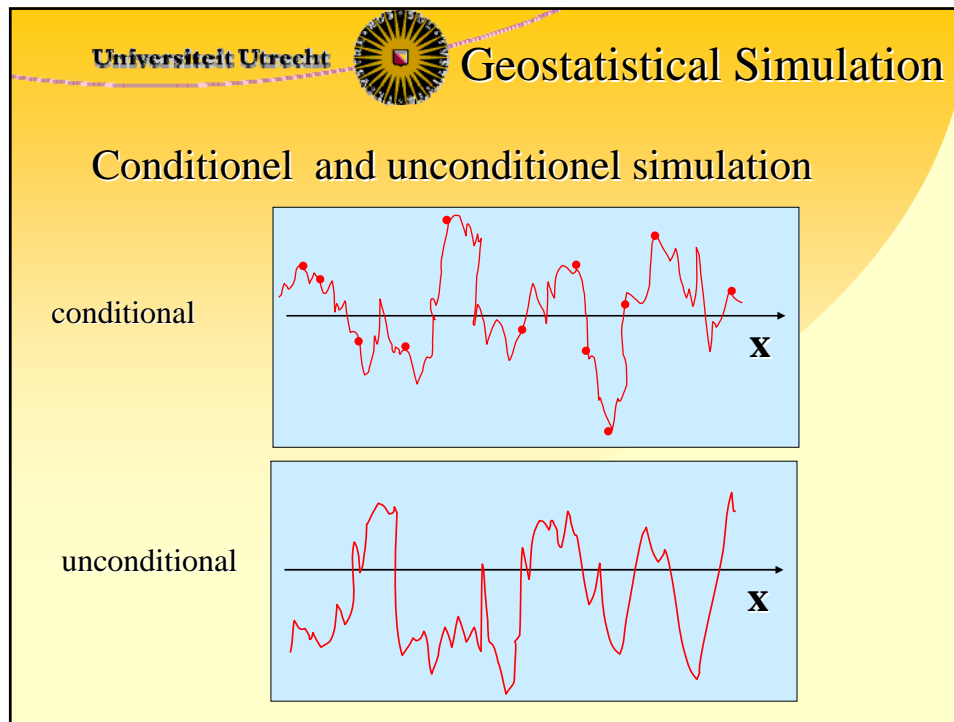


Geostatistical Simulation



Geostatistical Simulation







Conditionel simulation or kriging?

- If point-operation: kriging and conditional pdf

$$Y(\mathbf{x}_0) = g[Z(\mathbf{x}_0)]$$

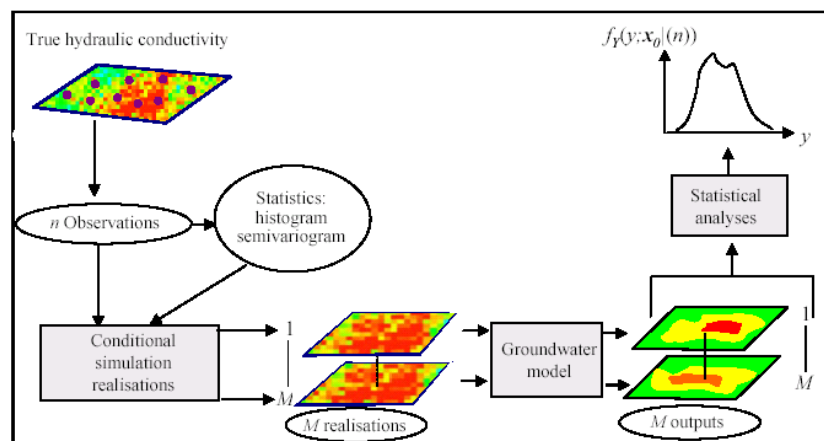
- If neighborhood operation: conditional simulation

$$Y(\mathbf{x}_0) = g[Z(\mathbf{x}_1), \dots, Z(\mathbf{x}_N)]$$

Includes partial differential equations!



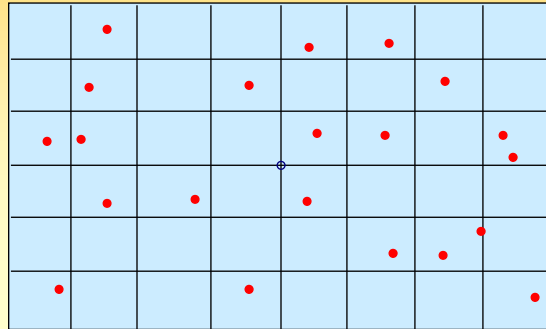
Monte Carlo Analysis or Monte Carlo Simulation





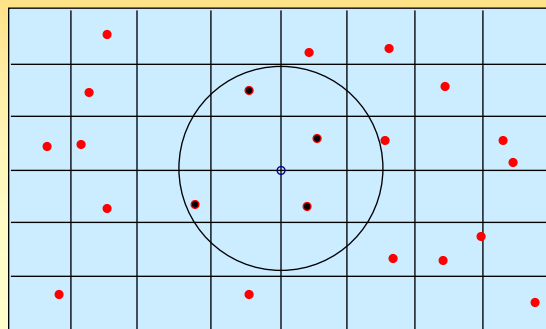
Sequential Gaussian Simulation

1. Define a simulation grid and visit grid points at random



Sequential Gaussian Simulation

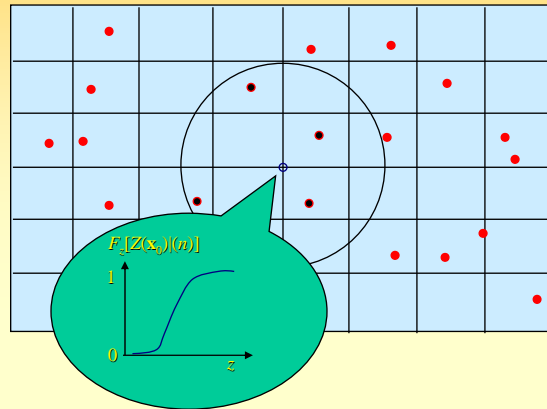
2. Select observations within search radius





Sequential Gaussian Simulation

3. Estimate the conditional cpdf from kriging

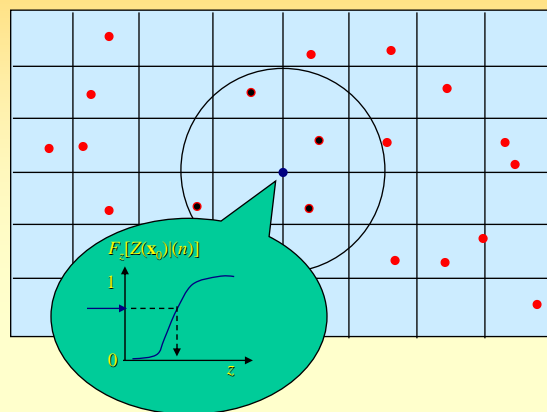


$F_z[Z(\mathbf{x}_0)|(n)]$ using MultiGaussian kriging



Sequential Gaussian Simulation

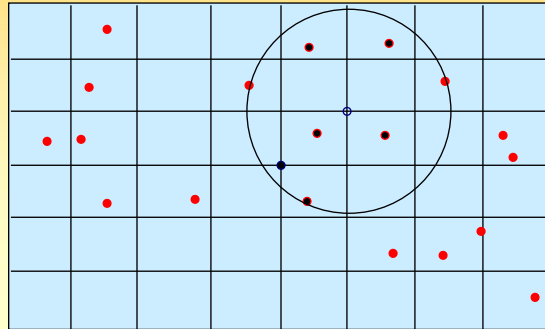
4. Draw a random variable from the cpdf and add it to the data set





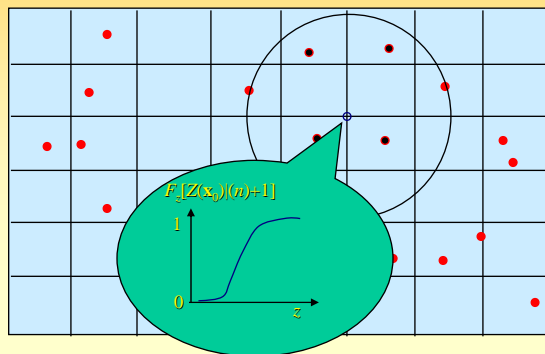
Sequential Gaussian Simulation

5. Go to the next grid location



Sequential Gaussian Simulation

6. Estimate the conditional cpdf using kriging

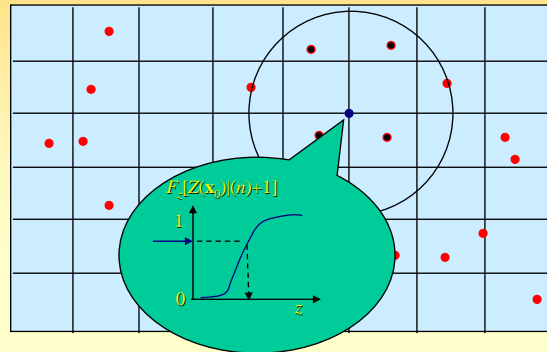


$F_z[Z(\mathbf{x}_0)|(n)+1]$ via MultiGaussian kriging
kriging using observations + previously simulated nodes



Sequential Gaussian Simulation

7. Draw a random variable from the cpdf and add it to the data set



Sequential Gaussian Simulation

8. Next location on the grid, etc. etc.

