Supplementary material for

Propagation of measurement error in opinion dynamics models: the case of the Deffuant mode

In this file we quickly repeat the analysis of the main article. However, instead of analyzing the Deffuant model for a relatively short time span, we analyze it until convergence of the model.

First of all, we plot the dependence of the prediction error to the main internal parameters (except, of course, Tr).

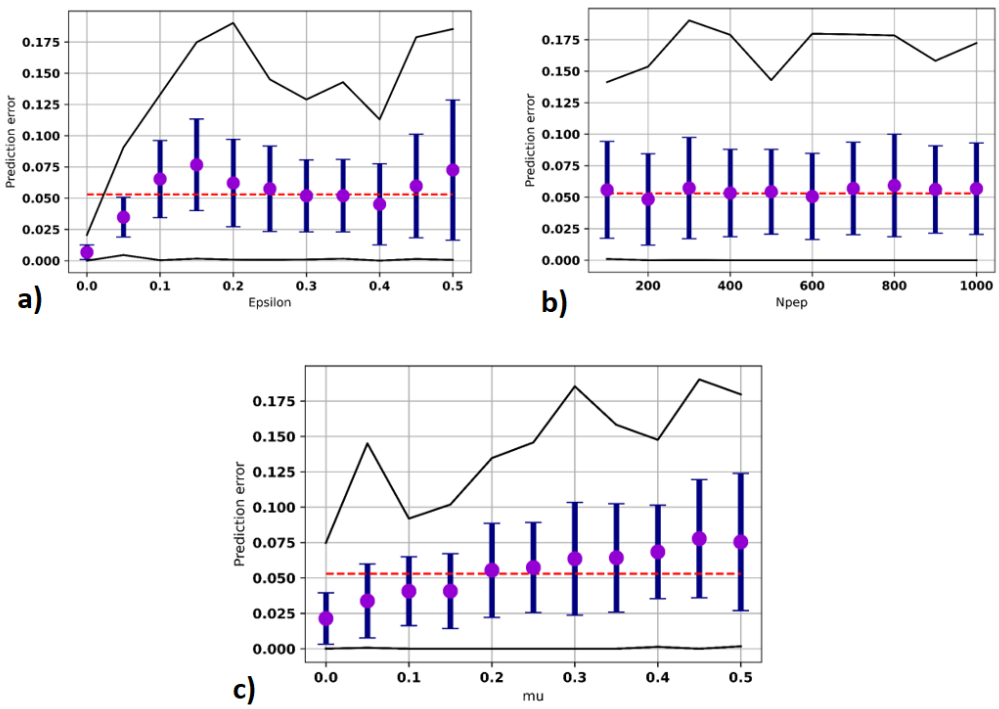

Figure 1: prediction error depending on (a) epsilon, (b) Number of agents and (c) mu.

Also in this case, the prediction depends on both epsilon and mu, but not on the number of agents.

Then we repeat the analysis for noise, binning and distortions.

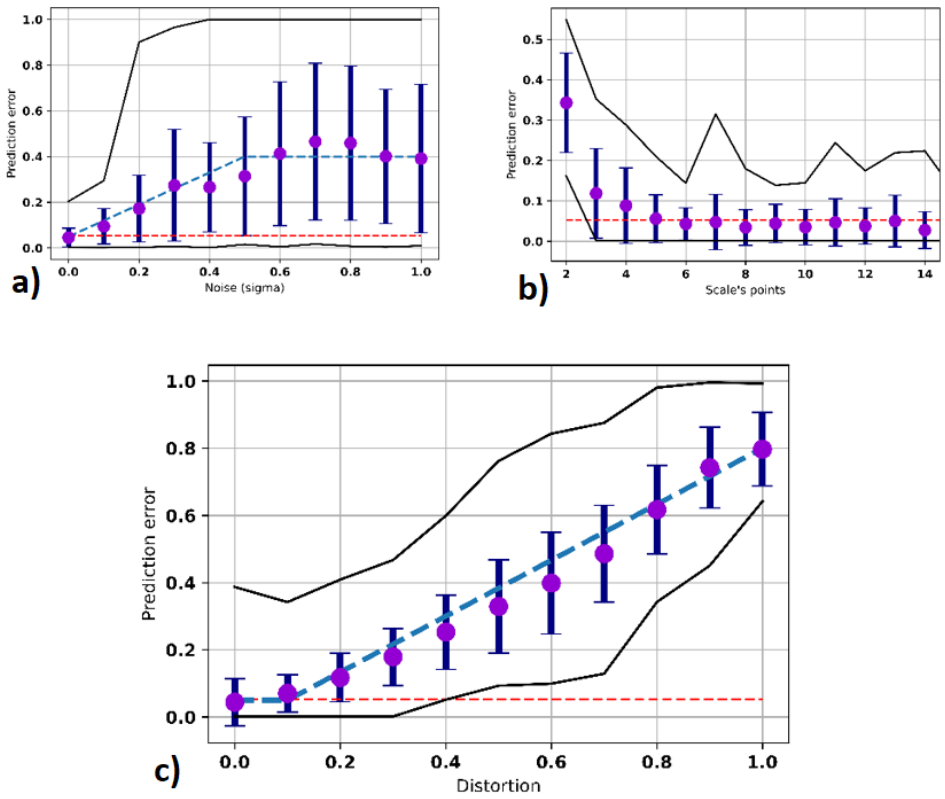

Figure 2: Prediction error in the case of (a) noise, (b) binning and (c) distortions

As we can see results are comparable with the case of finite time (i.e. the ones in the main paper). This is due to the fact that predictions in the Deffuant model strongly depend on the initial distribution (as in many other models). Therefore, measurement errors (which translate into changes of the initial distribution) can strongly affect the Deffuant model also when its predictions are carried until convergence.