# Lesson 1:

# Introduction to Simulation-based Inference for Epidemiological Dynamics

## Aaron A. King and Edward L. Ionides

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## 1 Introduction

#### Objectives for this lesson

- To understand the motivations for simulation-based inference in the study of epidemiological and ecological systems.
- To introduce the class of partially observed Markov process (POMP) models.
- To introduce the **pomp** R package.

## 1.1 What makes epidemiological inference hard?

#### Epidemiological and Ecological Dynamics

- Ecological systems are complex, open, nonlinear, and nonstationary.
- "Laws of Nature" are unavailable except in the most general form.
- It is useful to model them as stochastic systems.
- For any observable phenomenon, multiple competing explanations are possible.
- Central scientific goals:
  - Which explanations are most favored by the data?
  - Which kinds of data are most informative?

- Central applied goals:
  - How to design ecological or epidemiological intervention?
  - How to make accurate forecasts?
- Time series are particularly useful sources of data.

#### Obstacles to inference

Obstacles for **ecological** modeling and inference via nonlinear mechanistic models enumerated by Bjørnstad and Grenfell (2001)

- 1. Combining measurement noise and process noise.
- 2. Including covariates in mechanistically plausible ways.
- 3. Using continuous-time models.
- 4. Modeling and estimating interactions in coupled systems.
- 5. Dealing with unobserved variables.
- 6. Modeling spatial-temporal dynamics.

The same issues arise for **epidemiological** modeling and inference via nonlinear mechanistic models. The *partially observed Markov process* modeling framework we focus on in this course addresses most of these problems effectively.

#### 1.2 Course overview

#### Course objectives

- 1. To show how stochastic dynamical systems models can be used as scientific instruments.
- 2. To teach statistically and computationally efficient approaches for performing scientific inference using POMP models.
- 3. To give students the ability to formulate models of their own.
- 4. To give students opportunities to work with such inference methods.
- 5. To familiarize students with the **pomp** package.
- 6. To provide documented examples for adaptation and re-use.

#### Questions and answers

- 1. How does one combine various data types to quantify asymptomatic COVID-19 infections? (Subramanian et al., 2021)
- 2. How effective have various non-pharmaceutical interventions been at controlling SARS-CoV-2 spread in hospitals? (Shirreff et al., 2022)
- 3. How does one use incidence and mobility data to infer key epidemiological parameters? (Andrade and Duggan, 2022)
- 4. How does one make forecasts for an outbreak of an emerging infectious disease? (King et al., 2015)
- 5. How does one build a system for real-time surveillance of COVID-19 using epidemiological and mobility data? (Fox et al., 2022)

- 6. What strategies are effective at containing mumps spread on college campuses? (Shah et al., 2022)
- 7. What explains the resurgence of pertussis in countries with sustained high vaccine coverage? (Domenech de Cellès *et al.*, 2018)
- 8. Do subclinical infections of pertussis play an important epidemiological role? (Lavine et al., 2013)
- 9. Can serotype-specific immunity explain the strain dynamics of human enteroviruses? (Pons-Salort and Grassly, 2018)
- 10. How does dynamic variation in individual sexual behavior contribute to the HIV epidemic? How does this compare to the role of heterogeneity between individuals? (Romero-Severson et al., 2015)
- 11. What is the contribution of adults to polio transmission? (Blake et al., 2014)
- 12. What explains the interannual variability of malaria? (Laneri et al., 2010)
- 13. Can hydrology explain the seasonality of cholera? (Baracchini et al., 2017)
- 14. What roles are played by asymptomatic infection and waning immunity in cholera epidemics? (King et al., 2008)

# 2 Partially observed Markov processes

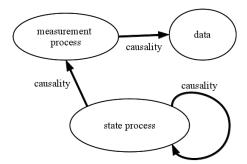
## 2.1 Mathematical definitions

#### Partially observed Markov process (POMP) models

- Data  $y_1^*, \ldots, y_N^*$  collected at times  $t_1 < \cdots < t_N$  are modeled as noisy, incomplete, and indirect observations of a Markov process  $\{X(t), t \geq t_0\}$ .
- This is a **partially observed Markov process (POMP)** model, also known as a hidden Markov model or a state space model.
- $\{X(t)\}\$  is Markov if the history of the process,  $\{X(s), s \leq t\}$ , is uninformative about the future of the process,  $\{X(s), s \geq t\}$ , given the current value of the process, X(t).
- If all quantities important for the dynamics of the system are placed in the **state**, X(t), then the Markov property holds by construction.
- Systems with delays can usually be rewritten as Markovian systems, at least approximately.
- An important special case: any system of differential equations dx/dt = f(x) is Markovian.
- POMP models can include all the features desired by Bjørnstad and Grenfell (2001).

#### Schematic of the structure of a POMP

- Arrows in the following diagram show causal relations.
- A key perspective to keep in mind is that the model is to be viewed as the process that generated the data.
- That is: the data are viewed as one realization of the model's stochastic process.



#### Notation for POMP models

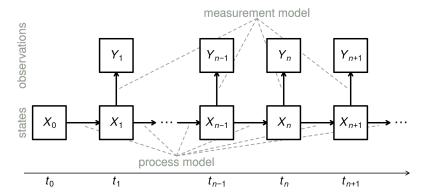
- Write  $X_n = X(t_n)$  and  $X_{0:N} = (X_0, \dots, X_N)$ . Let  $Y_n$  be a random variable modeling the observation at time  $t_n$ .
- The one-step transition density,  $f_{X_n|X_{n-1}}(x_n|x_{n-1};\theta)$ , together with the measurement density,  $f_{Y_n|X_n}(y_n|x_n;\theta)$  and the initial density,  $f_{X_0}(x_0;\theta)$ , specify the entire POMP model.
- The joint density  $f_{X_{0:N},Y_{1:N}}(x_{0:N},y_{1:N};\theta)$  can be written as

$$f_{X_0}(x_0;\theta) \prod_{n=1}^{N} f_{X_n|X_{n-1}}(x_n|x_{n-1};\theta) f_{Y_n|X_n}(y_n|x_n;\theta)$$

 $\bullet$  The marginal density for  $Y_{1:N}$  evaluated at the data,  $y_{1:N}^*,$  is

$$f_{Y_{1:N}}(y_{1:N}^*;\theta) = \int f_{X_{0:N},Y_{1:N}}(x_{0:N},y_{1:N}^*;\theta) dx_{0:N}$$

## Another POMP model schematic



• The state process,  $X_n$ , is Markovian, i.e.,

$$f_{X_n|X_{0:n-1},Y_{1:n-1}}(x_n|x_{0:n-1},y_{1:n-1}) = f_{X_n|X_{n-1}}(x_n|x_{n-1}).$$

• Moreover,  $Y_n$ , depends only on the state at that time:

$$f_{Y_n|X_{0:N},Y_{1:n-1}}(y_n|x_{0:n},y_{1:n-1}) = f_{Y_n|X_n}(y_n|x_n), \text{ for } n=1,\ldots,N.$$

## 2.2 From math to algorithms

#### Moving from math to algorithms for POMP models

We specify some basic model components which can be used within algorithms:

- 'rprocess': a draw from  $f_{X_n|X_{n-1}}(x_n|x_{n-1};\theta)$
- 'dprocess': evaluation of  $f_{X_n|X_{n-1}}(x_n|x_{n-1};\theta)$
- 'rmeasure': a draw from  $f_{Y_n|X_n}(y_n|x_n;\theta)$
- 'dmeasure': evaluation of  $f_{Y_n|X_n}(y_n|x_n;\theta)$
- 'rinit': a draw from  $f_{X_0}(x_0;\theta)$

These basic model components define the specific POMP model under consideration.

#### What is a simulation-based method?

- Simulating random processes is often much easier than evaluating their transition probabilities.
- In other words, we may be able to write rprocess but not dprocess.
- Simulation-based methods require the user to specify rprocess but not dprocess.
- Plug-and-play, likelihood-free and equation-free are alternative terms for "simulation-based" methods.
- Much development of simulation-based statistical methodology has occurred in the past decade.

## 3 The pomp package

## The pomp package for POMP models

- **pomp** is an R package for data analysis using partially observed Markov process (POMP) models (King *et al.*, 2016).
- Note the distinction: lower case pomp is a software package; upper case POMP is a class of models.
- pomp builds methodology for POMP models in terms of arbitrary user-specified POMP models.
- pomp provides tools, documentation, and examples to help users specify POMP models.
- **pomp** provides a platform for modification and sharing of models, data-analysis workflows, and methodological development.

#### Structure of the pomp package

It is useful to divide the **pomp** package functionality into different levels:

- Basic model components
- Workhorses
- Elementary POMP algorithms
- Inference algorithms

#### Basic model components

Basic model components are user-specified procedures that perform the elementary computations that specify a POMP model. There are nine of these:

- 'rinit': simulator for the initial-state distribution, i.e., the distribution of the latent state at time  $t_0$ .
- 'rprocess' and 'dprocess': simulator and density evaluation procedure, respectively, for the process model.
- 'rmeasure' and 'dmeasure': simulator and density evaluation procedure, respectively, for the measurement model.
- 'rprior' and 'dprior': simulator and density evaluation procedure, respectively, for the prior distribution.
- 'skeleton': evaluation of a deterministic skeleton.
- 'partrans': parameter transformations.

The scientist must specify whichever of these basic model components are required for the algorithms that the scientist uses.

#### Workhorses

Workhorses are R functions, built into the package, that cause the basic model component procedures to be executed.

- Each basic model component has a corresponding workhorse.
- Effectively, the workhorse is a vectorized wrapper around the basic model component.
- For example, the rprocess() function uses code specified by the rprocess model component, constructed via the rprocess argument to pomp().
- The rprocess model component specifies how a single trajectory evolves at a single moment of time. The rprocess() workhorse combines these computations for arbitrary collections of times and arbitrary numbers of replications.

## Elementary POMP algorithms

These are algorithms that interrogate the model or the model/data confrontation without attempting to estimate parameters. There are currently four of these:

- simulate performs simulations of the POMP model, i.e., it samples from the joint distribution of latent states and observables.
- pfilter runs a sequential Monte Carlo (particle filter) algorithm to compute the likelihood and (optionally) estimate the prediction and filtering distributions of the latent state process.
- probe computes one or more uni or multivariate summary statistics on both actual and simulated data.
- spect estimates the power spectral density functions for the actual and simulated data.

#### POMP inference algorithms

These are procedures that build on the elementary algorithms and are used for estimation of parameters and other inferential tasks. There are currently ten of these:

- abc: approximate Bayesian computation
- bsmc2: Liu-West algorithm for Bayesian SMC
- pmcmc: a particle MCMC algorithm
- mif2: iterated filtering (IF2)
- enkf, eakf ensemble and ensemble adjusted Kalman filters
- traj\_objfun: trajectory matching
- spect\_objfun: power spectrum matching
- probe\_objfun: probe matching
- nlf\_objfun: nonlinear forecasting

Objective function methods: among the estimation algorithms just listed, four are methods that construct stateful objective functions that can be optimized using general-purpose numerical optimization algorithms such as optim, subplex, or the optimizers in the nloptr package.

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