

# Code for “Sequential Monte Carlo methods for mixtures with normalized random measures with independent increment priors

J. E. Griffin\*

## 1 Introduction

All the code uses the methods developed in the paper and assumes the following infinite mixture model for a sample of data  $y_1, \dots, y_n$ . Either

$$y_i \sim N(\theta_i, a\sigma^2)$$

$$\theta_i \sim \text{DP}(M, H)$$

where  $\text{DP}(M, H)$  represents a Dirichlet process (DP) with mass parameter  $M$  and centring measure  $H = N(\mu, (1 - a)\sigma^2)$  or

$$y_i \sim N(\theta_i, a\sigma^2)$$

$$\theta_i \sim \text{NGG}(\gamma, M, H)$$

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\*Jim Griffin is Professor, School of Mathematics, Statistics and Actuarial Science, University of Kent, Canterbury, CT2 7NF, U.K. (Email: J.E.Griffin-28@kent.ac.uk)

where  $\text{NGG}(\gamma, M, H)$  is a Normalized Generalized Gamma process (NGGP) with shape parameter  $\gamma$ , mass parameter  $M$  and centring measure  $H = \text{N}(0, (1 - a)\sigma^2)$  for which the unnormalized random measure has Lévy measure  $\rho(x) = \frac{M}{\Gamma(1-\gamma)} x^{-1-\gamma} \exp\{-x\}$ . All particle filter use the stratified re-sampling method (Carpenter, Clifford and Fearnhead, 1999) to re-weight particles

The file `run_code.m` contains code for running all code on the galaxy data set used in the paper.

## 1.1 Methods for conjugate models

```
[s] = algorithm1_DP(data, mu, sigmasq, a, M, numbofparts)
[s] = algorithm3_DP(data, mu, sigmasq, a, M, numbofparts)
[s] = algorithm3_NGG(data, mu, sigmasq, a, gamma, M, numbofparts)
```

### Inputs

`data` – the sample  $y_1, \dots, y_n$ .

`mu` – the value of the parameter  $\mu$

`sigmasq` – the value of the parameter  $\sigma^2$ .

`a` – the value of the parameter  $a$ .

`gamma` – the value of the parameter  $\gamma$  (for NGGP models)

`M` – the value of the parameter  $M$ .

`numbofparts` – the number of particles,  $N$ .

## Outputs

$s$  – a  $(N \times n)$ -dimensional matrix whose  $i$ -th row is the cluster configuration  $s$  for the  $i$ -th particle.

## 1.2 Methods for non-conjugate models

```
[s] = algorithm2_DP(data, mu, sigmasq, a, M, m, numbofparts)
[s] = algorithm4_DP(data, mu, sigmasq, a, M, m, numbofparts)
[s] = algorithm4_NGG(data, mu, sigmasq, a, gamma, M, m, numbofparts)
```

## Inputs

`data` – the sample  $y_1, \dots, y_n$ .

`mu` – the value of the parameter  $\mu$

`sigmasq` – the value of the parameter  $\sigma^2$ .

`a` – the value of the parameter  $a$ .

`gamma` – the value of the parameter  $\gamma$  (for NGGP models)

`M` – the value of the parameter  $M$ .

`m` – the number of empty clusters generated.

`numbofparts` – the number of particles,  $N$ .

## Outputs

$s$  – a  $(N \times n)$ -dimensional matrix whose  $i$ -th row is the cluster configuration  $s$  for the  $i$ -th particle.

### 1.3 Methods for conjugate models with parameter updating

```
[s, a] = algorithm3_DP_param(data, mu, sigmasq, M, numbofparts)
```

```
[s, a] = algorithm3_NGG_param(data, mu, sigmasq, gamma, M, numbofparts)
```

#### Inputs

`data` – the sample  $y_1, \dots, y_n$ .

`mu` – the value of the parameter  $\mu$

`sigmasq` – the value of the parameter  $\sigma^2$ .

`gamma` – the value of the parameter  $\gamma$  (for NGGP models)

`M` – the value of the parameter  $M$ .

`numbofparts` – the number of particles,  $N$ .

#### Outputs

`s` – an  $(N \times n)$ -dimensional matrix whose  $i$ -th row contains the cluster configuration  $s$  for the  $i$ -th particle.

`a` – an  $N$ -dimensional vector whose  $i$ -th element contains the value of  $a$  for the  $i$ -th particle.

### 1.4 Methods for non-conjugate models with parameter updating

```
[s, a] = algorithm4_DP_param(data, mu, sigmasq, M, m, numbofparts)
```

```
[s, a] = algorithm4_NGG_param(data, mu, sigmasq, gamma, M, m, numbofparts)
```

## Inputs

`data` – the sample  $y_1, \dots, y_n$ .

`mu` – the value of the parameter  $\mu$

`sigmasq` – the value of the parameter  $\sigma^2$ .

`gamma` – the value of the parameter  $\gamma$  (for NGGP models)

`M` – the value of the parameter  $M$ .

`m` – the number of empty clusters generated.

`numbofparts` – the number of particles,  $N$ .

## Outputs

`s` – a  $(N \times n)$ -dimensional matrix whose  $i$ -th row is the cluster configuration  $s$  for the  $i$ -th particle.

`a` – an  $N$ -dimensional vector whose  $i$ -th element contains the value of  $a$  for the  $i$ -th particle.

## References

Carpenter, J., Clifford, P. and Fearnhead, P. (1999). An improved particle filter for non-linear problems. *IEE proceedings - Radar, Sonar and Navigation*, 146, 2–7.