

# Mathematical notation of the models

In “*Population dynamics of two deer species under predation and changing climate*”

Toivonen Pyry<sup>12\*</sup>, Aikio Sami<sup>1</sup>, Huitu Otso<sup>1</sup>, Mäntyniemi Samu<sup>1</sup>, Valtonen Mia<sup>1</sup>, Laaksonen Toni<sup>2</sup>

<sup>1</sup>Natural Resources Institute Finland, FI-00790 Helsinki, Finland

<sup>2</sup>Department of Biology, University of Turku, FI-20014 Turku, Finland

$i = 1, 2, 3 \dots N$

$X$  a matrix of size  $N \times 7$

$\beta$  a column vector of size  $7 \times 1$

$Z$  a matrix of size  $N \times K$

$s$  a column vector of size  $K \times 1$

where  $K$  is the number of knots in the spline.  $K = 8$  in both of the models.

## Model structure:

$y \sim \text{LogNormal}(\mu, \sigma)$

$\mu = X\beta + Zs$

where  $\beta$  contains the intercept and linear coefficients,  $X$  contains the variables and a column of 1s for the intercept,  $Z$  contains the basis functions and  $s$  the penalized spline coefficients

$\sigma = b_1 e^{-b_2 x_{\text{density}}} + e^{C_N}$

$C_N = 1_N C$

$C_N \sim \text{CAR}(\rho, \tau_c, A)$

where  $A$  represents the adjacency matrix and associated metrics,  $C$  is the population-level asymptote,  $1_N$  is a column vector of 1s of size  $N$ , and  $C_N$  is a column vector of individual asymptotes.

For more on CAR in Stan, see <https://github.com/mbjoseph/CARstan>

### **Splines (nonlinear, smooth effects):**

|  |   |
|--|---|
| $Z \ni R$  | basis function matrix                             |
| $S = Z_S \tau_S$   | penalized spline coefficients                     |
| $z_S \sim N(0, 1)$                                       | prior for standard. penalized spline coefficients |
| $\tau_{s1} \sim HalfNormal(0.5)$<br>(roe deer)           | prior for SDs of penalized spline coefficients    |
| $\tau_{s2} \sim HalfNormal(0.25)$<br>(white-tailed deer) | prior for SDs of penalized spline coefficients    |

### **Priors for linear effects:**

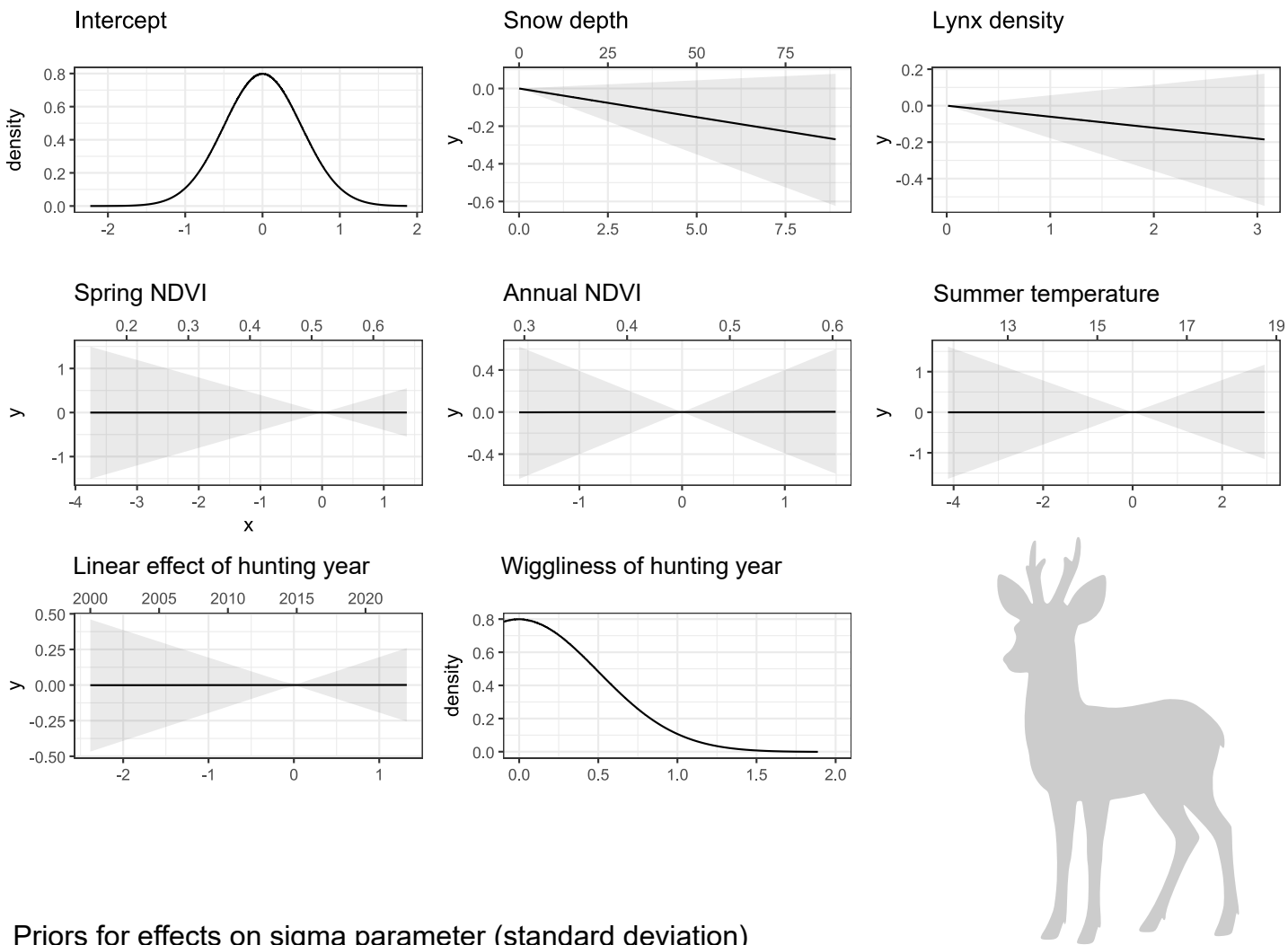
|                                    |  |
|------------------------------------|--|
| $\beta_0 \sim N(0, 0.5)$           | prior for intercept                    |
| $\beta_S \sim N(0, 0.1)$           | prior for linear effect of the splines |
| $\beta_{snow} \sim N(-0.03, 0.02)$ | prior for snow depth                   |
| $\beta_{lynx} \sim N(-0.06, 0.06)$ | prior for lynx density                 |
| $\beta_{spring} \sim N(0, 0.2)$    | prior for spring NDVI                  |
| $\beta_{NDVI} \sim N(0, 0.2)$      | prior for annual NDVI                  |
| $\beta_{summer} \sim N(0, 0.2)$    | prior for summer temperature           |

### **Priors for standard deviation:**

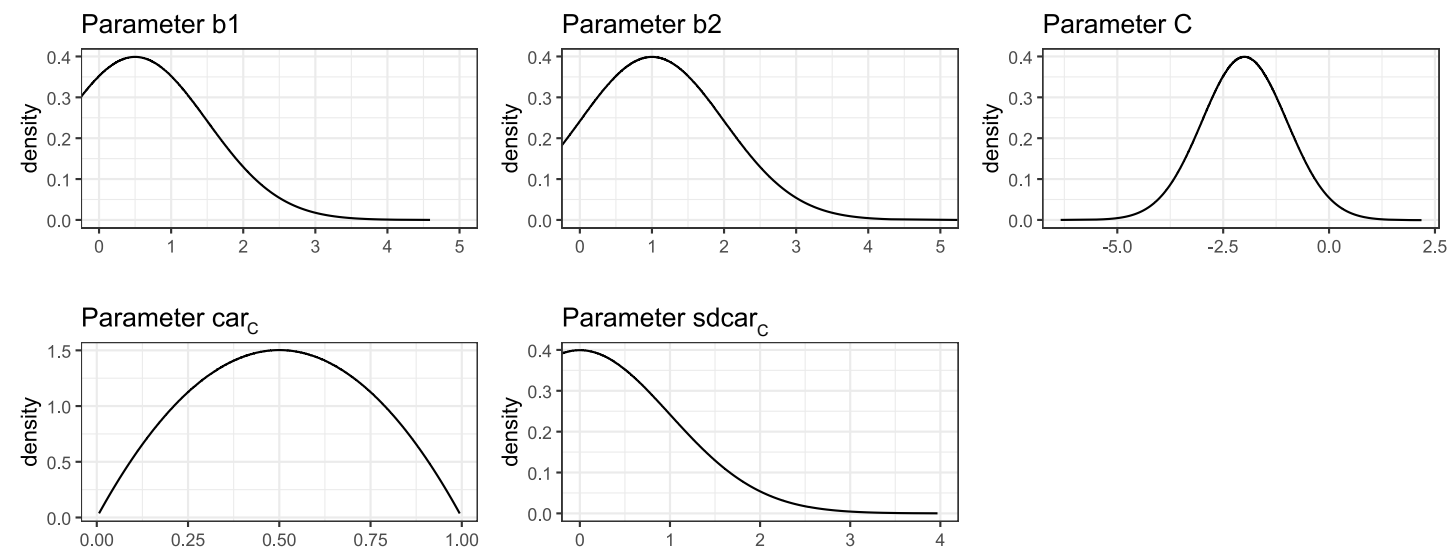
|                               |                                      |
|-------------------------------|--------------------------------------|
| $C \sim N(-2, 1), C < 0$      | prior for population-level asymptote |
| $b_1 \sim N(0.5, 1), b_1 > 0$ | prior for parameter $b_1$            |
| $b_2 \sim N(1, 1), b_2 > 0$   | prior for parameter $b_2$            |
| $\rho \sim Beta(2, 2)$        | prior for degree of autocorrelation  |
| $\tau_c \sim HalfNormal(1)$   | prior for parameter $\tau_c$         |

# Priors for roe deer model

## Priors for effects on mu parameter (mean)



## Priors for effects on sigma parameter (standard deviation)

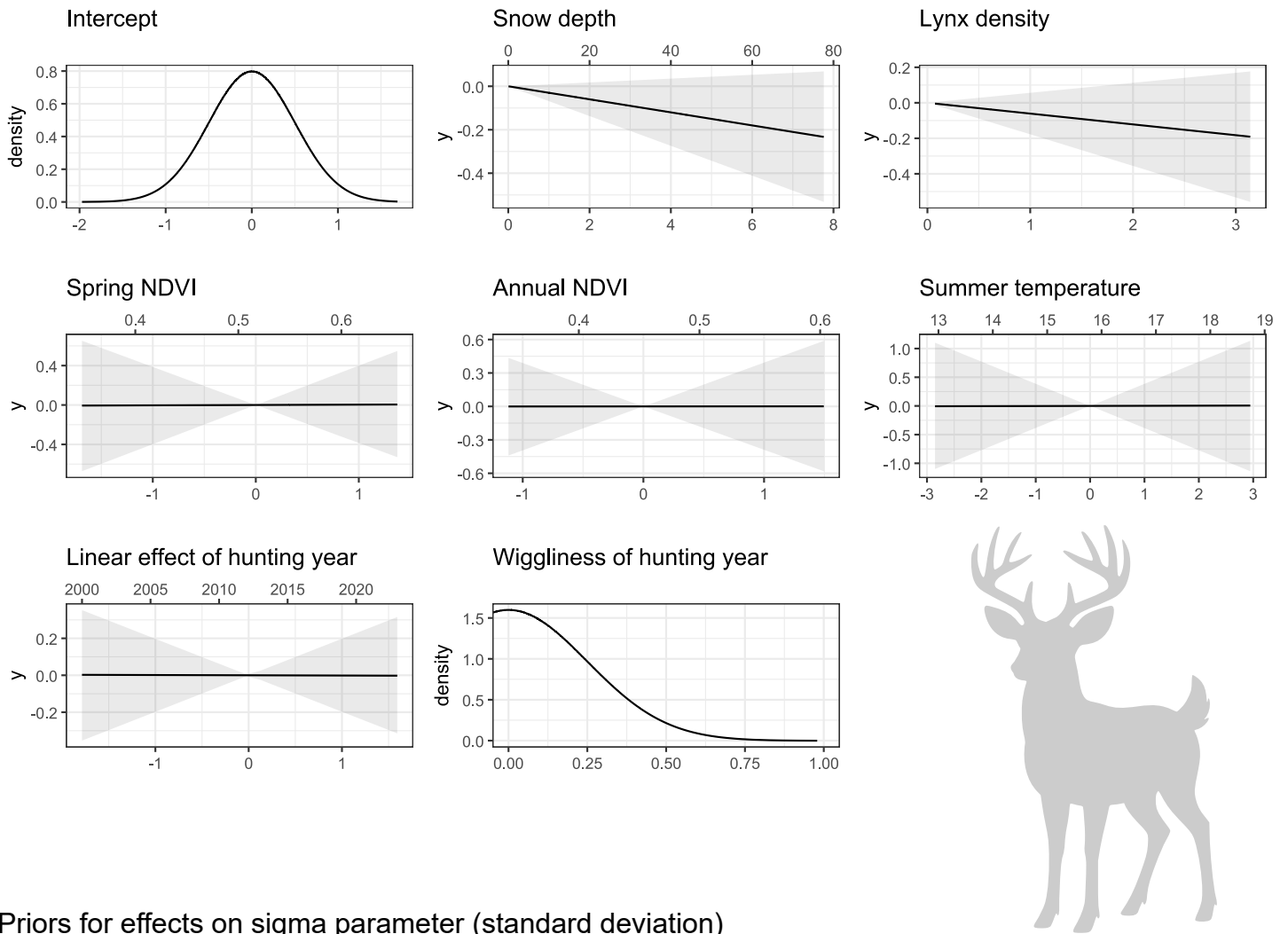


Prior information used in bayesian modelling. Priors are represented as prior distributions or prior effects with 95 % probability intervals. Upper x-axes represent backtransformed units.

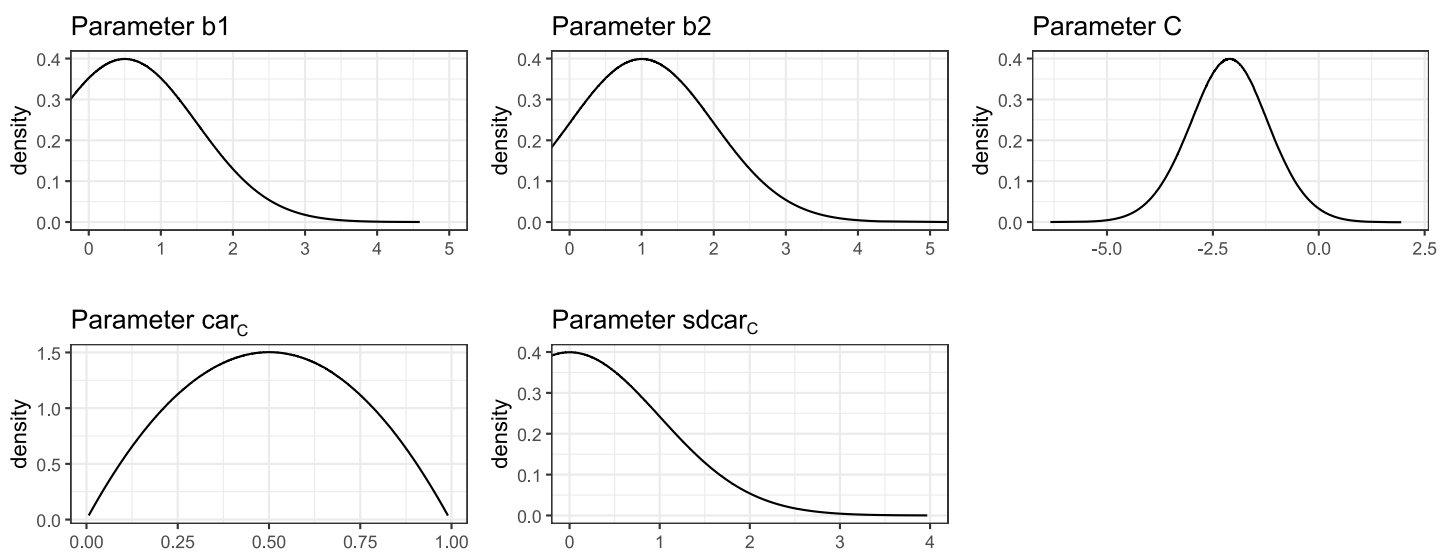
Parameter sdcar is the standard deviation of conditional autoregressive (CAR) structure. Car parameter is the parameter defining the degree of autocorrelation in the CAR stucture.

# Priors for white-tailed deer model

## Priors for effects on mu parameter (mean)



## Priors for effects on sigma parameter (standard deviation)



Prior information used in bayesian modelling. Priors are represented as prior distributions or prior effects with 95 % probability intervals. Upper x-axes represent backtransformed units.

Parameter sdcar is the standard deviation of conditional autoregressive (CAR) structure. Car parameter is the parameter defining the degree of autocorrelation in the CAR stucture.