

CCFs, Differencing, & AR(1) models

Lecture 08

Dr. Colin Rundel

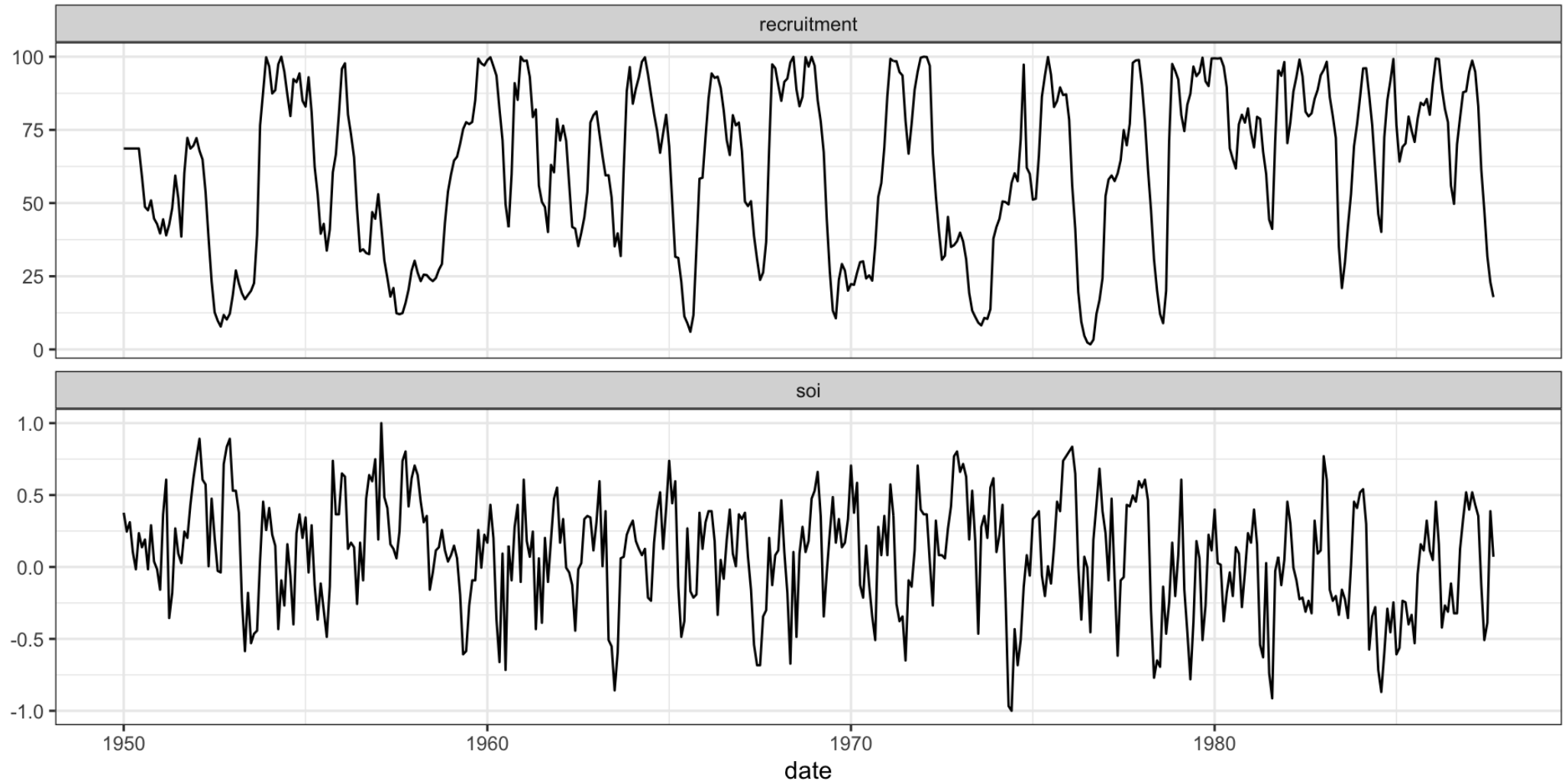
Lagged Predictors and CCFs

Southern Oscillation Index & Recruitment

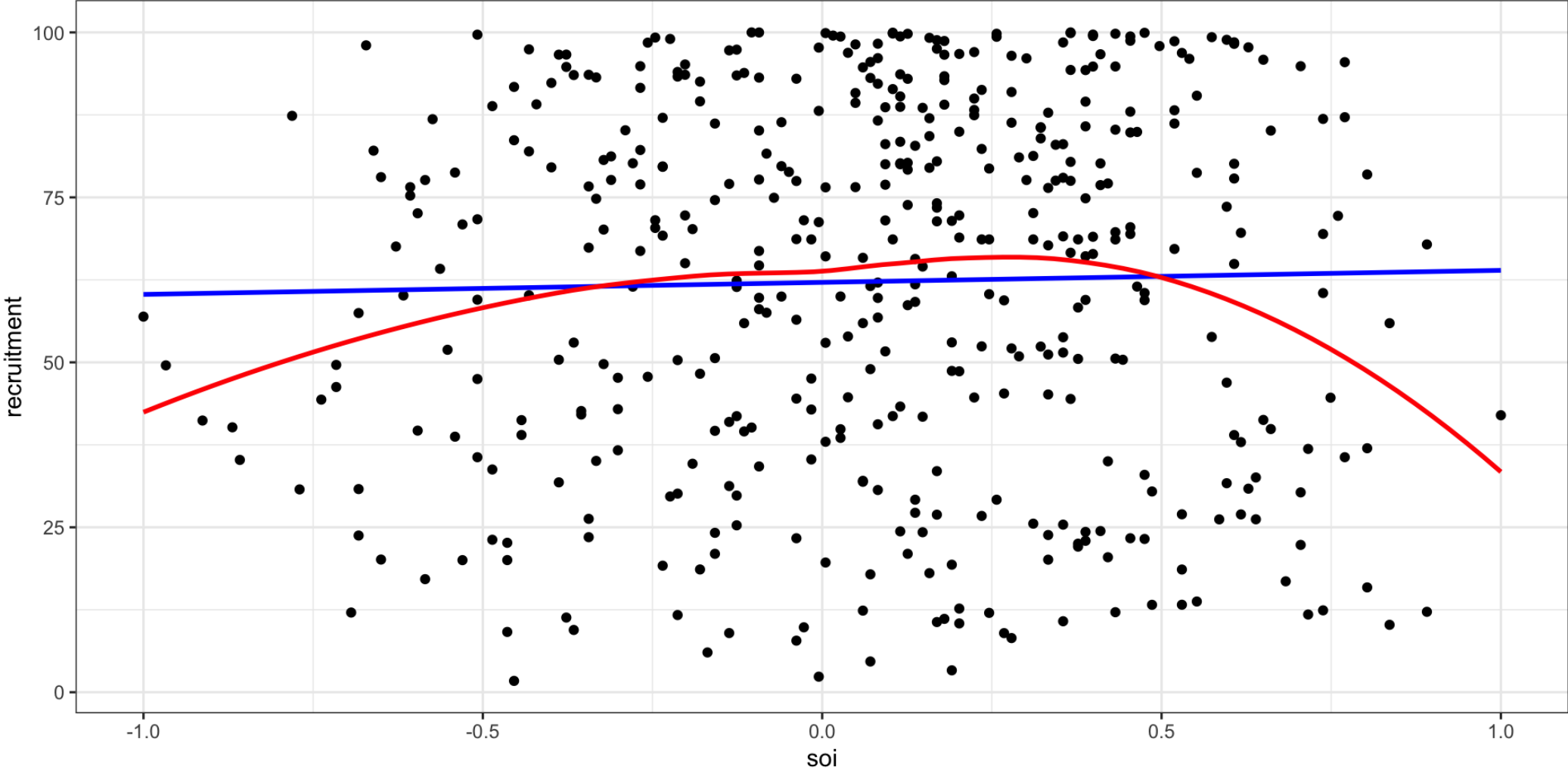
The Southern Oscillation Index (SOI) is an indicator of the development and intensity of El Niño (negative SOI) or La Niña (positive SOI) events in the Pacific Ocean. These data also included the estimate of “recruitment”, which indicate fish population sizes in the southern hemisphere.

```
# A tibble: 453 × 3
  date      soi recruitment
  <dbl>   <dbl>     <dbl>
1 1950     0.377     68.6
2 1950.    0.246     68.6
3 1950.    0.311     68.6
4 1950.    0.104     68.6
5 1950.   -0.016     68.6
6 1950.    0.235     68.6
7 1950.    0.137     59.2
8 1951.    0.191     48.7
9 1951.   -0.016     47.5
```

Time series

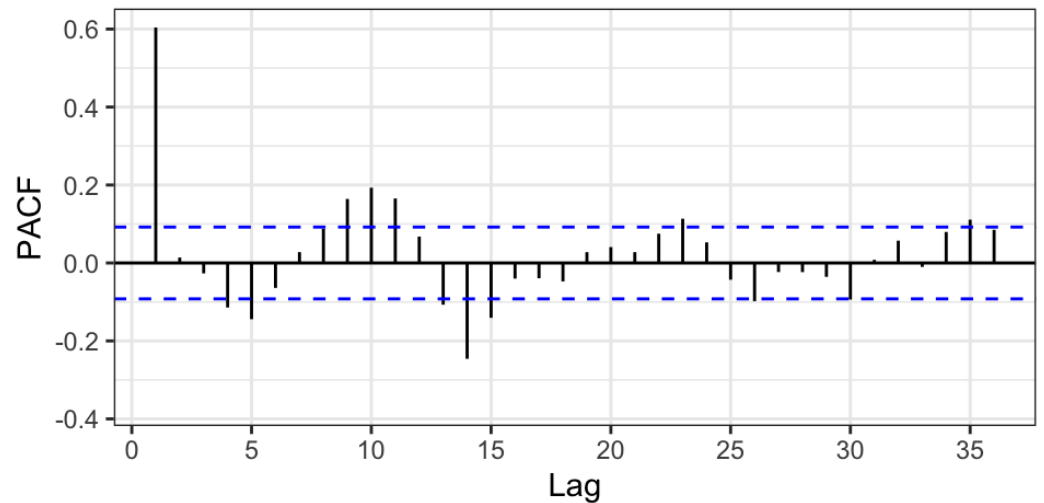
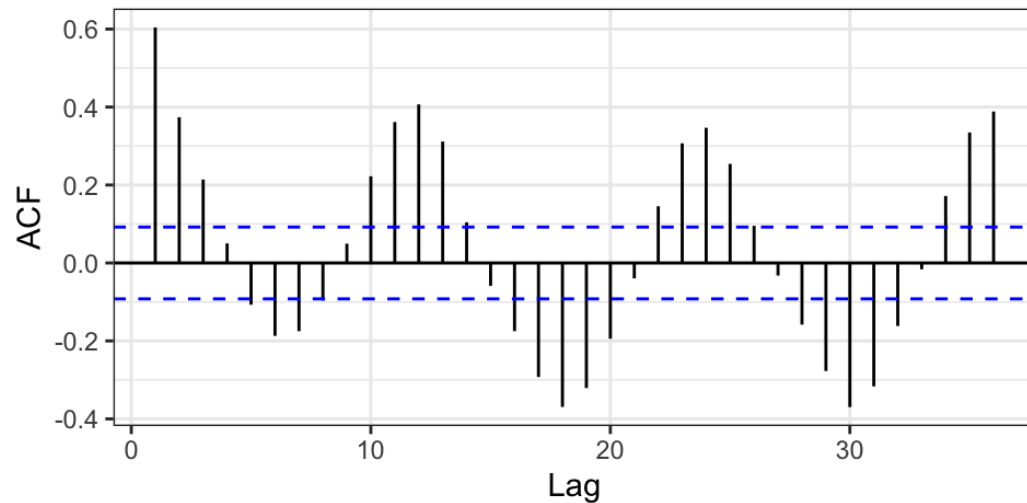
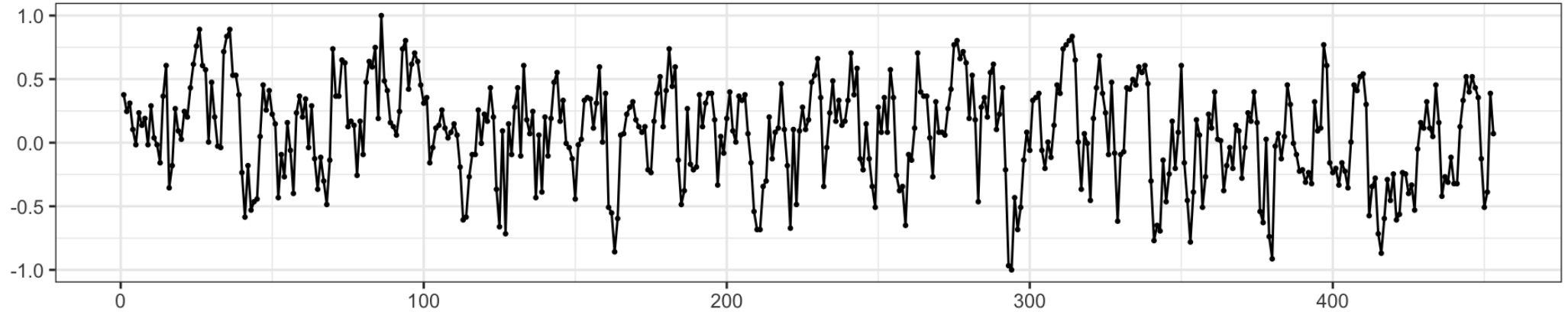


Relationship?



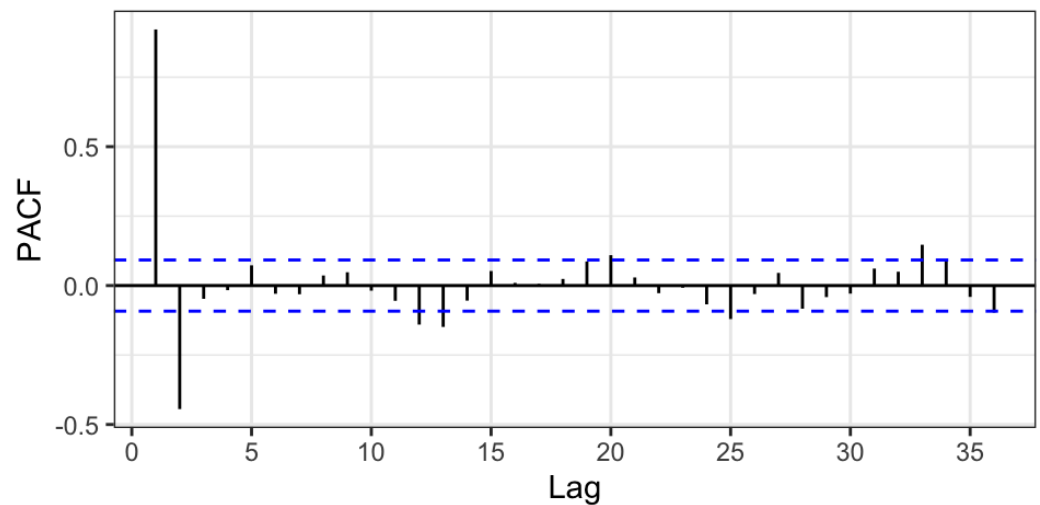
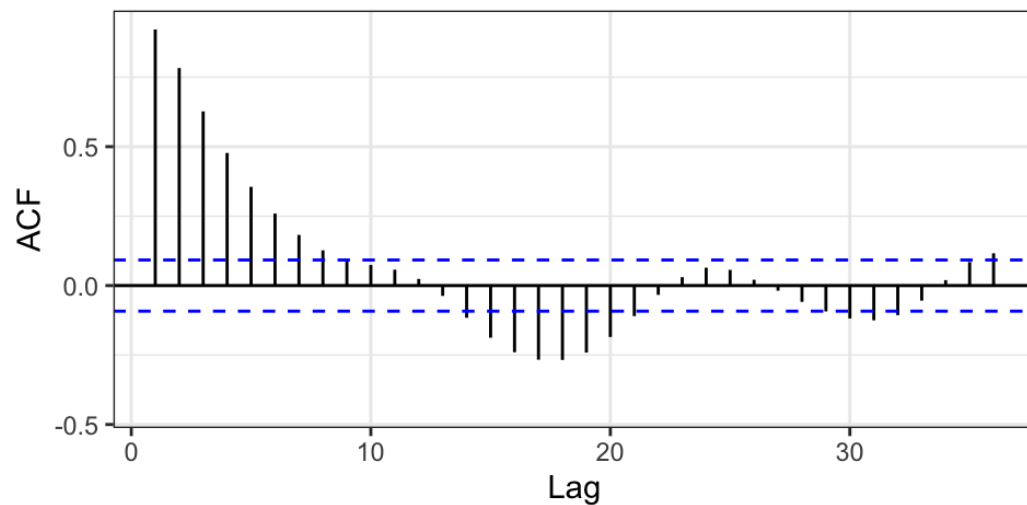
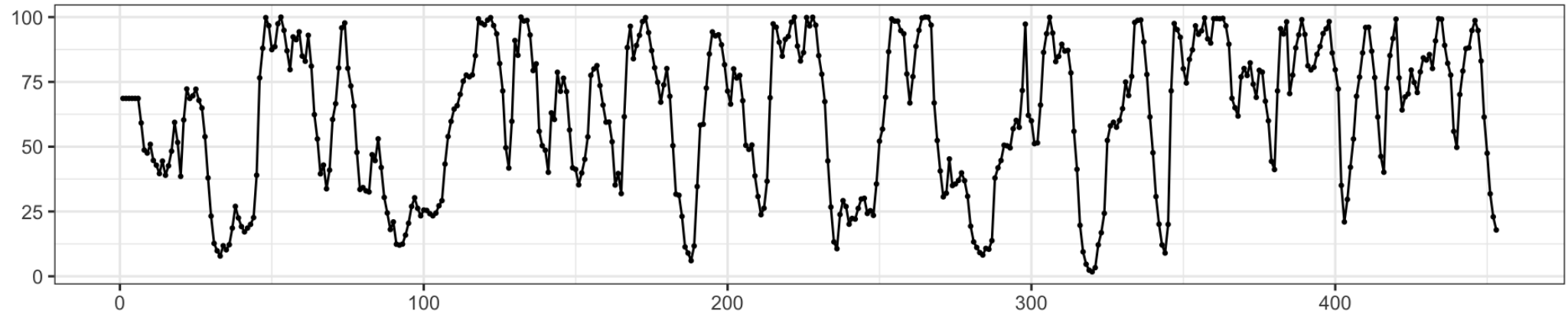
soi - ACF & PACF

```
1 forecast::ggtsdisplay(fish$soi, lag.max = 36)
```



recruitment - ACF & PACF

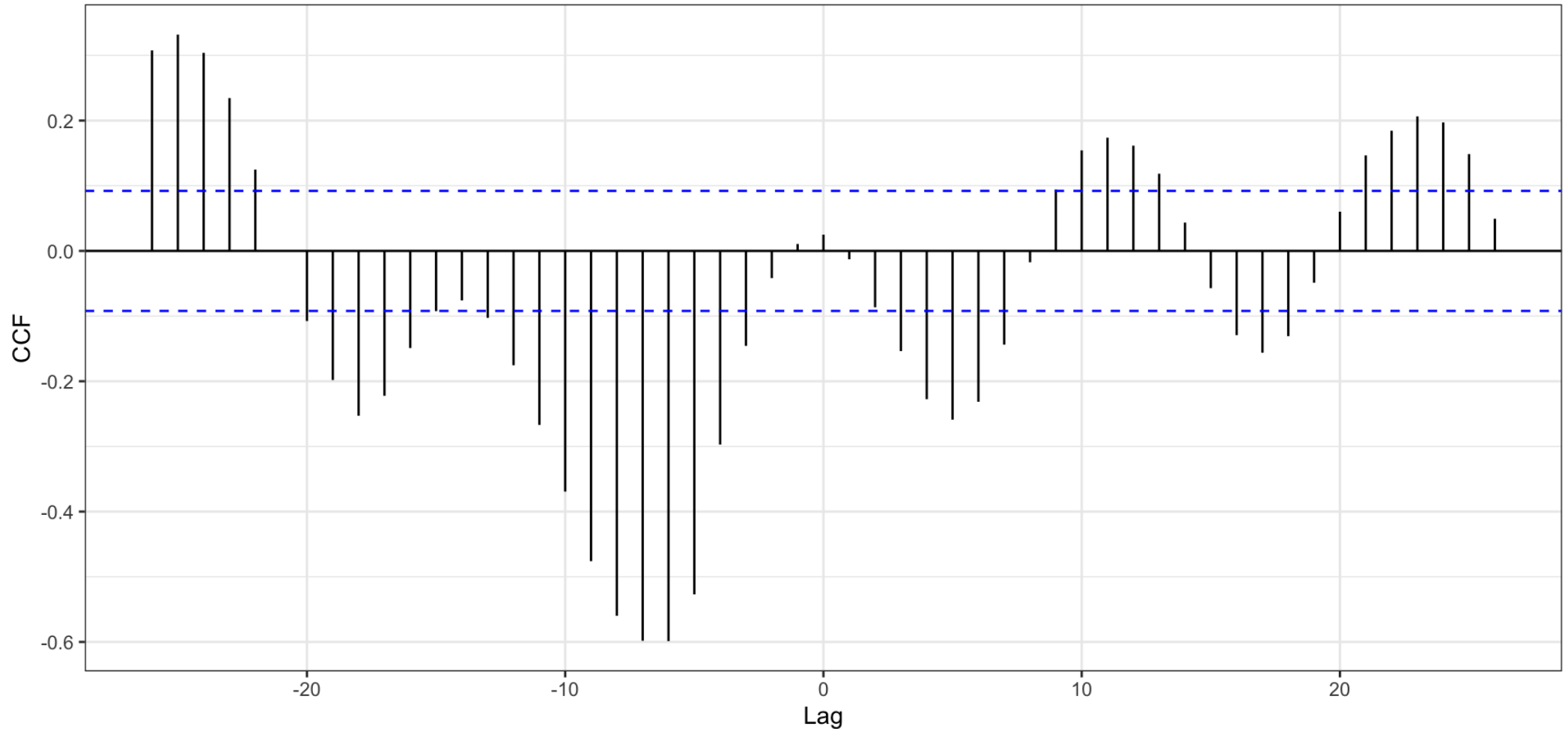
```
1 forecast::ggtsdisplay(fish$recruitment, lag.max = 36)
```



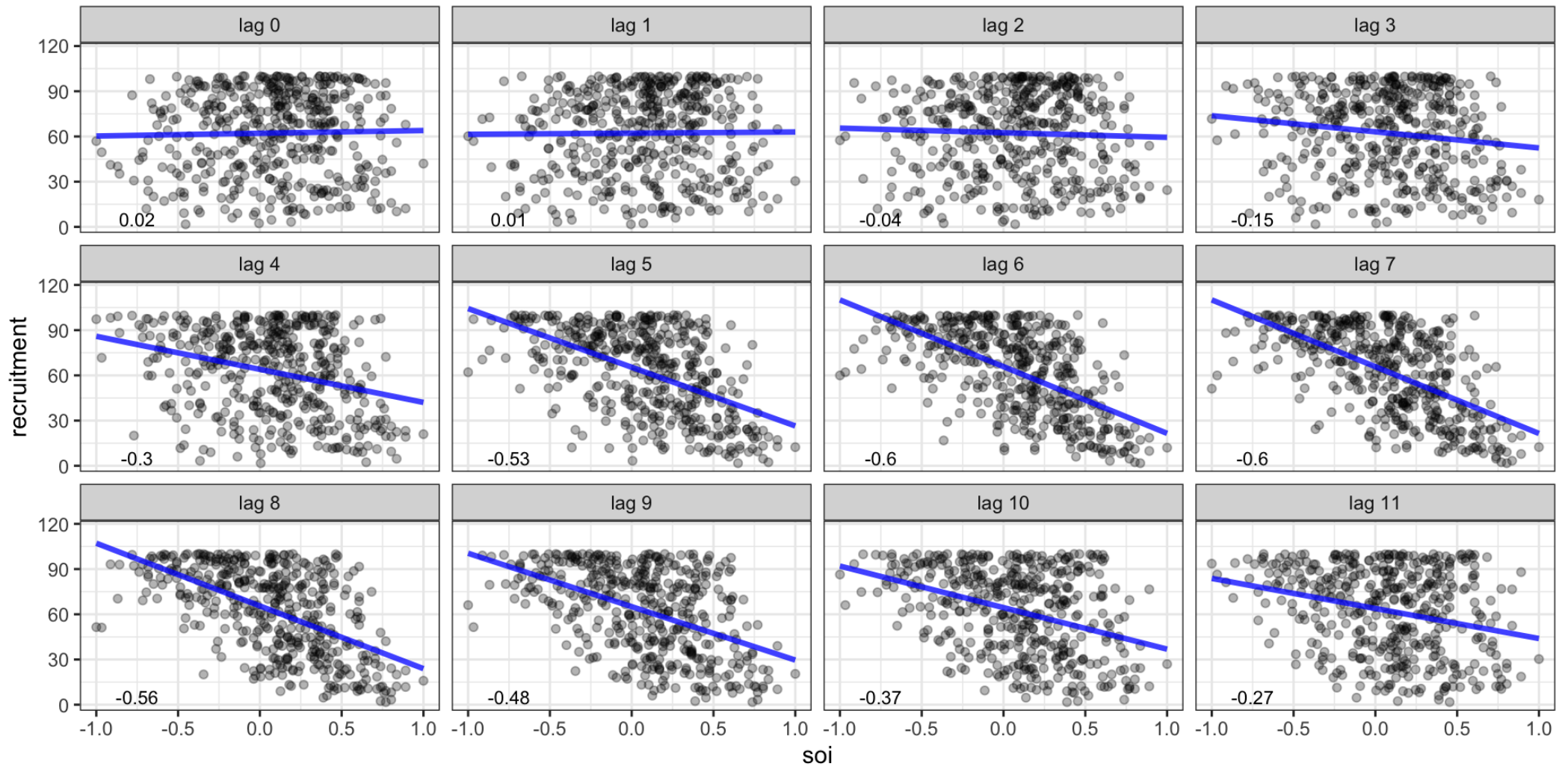
Cross correlation function

```
1 forecast::ggCcf(fish$soi, fish$recruitment)
```

Series: fish\$soi & fish\$recruitment



Cross correlation function - Scatter plots



The CCF gave us negative lags, why are we not considering them here?

Model

```
1 model1 = lm(recruitment~lag(soi,6), data=fish)
2 model2 = lm(recruitment~lag(soi,6)+lag(soi,7), data=fish)
3 model3 = lm(recruitment~lag(soi,5)+lag(soi,6)+lag(soi,7)+lag(soi,8), data=fish)
```

```
1 summary(model3)
```

Call:

```
lm(formula = recruitment ~ lag(soi, 5) + lag(soi, 6) + lag(soi,
  7) + lag(soi, 8), data = fish)
```

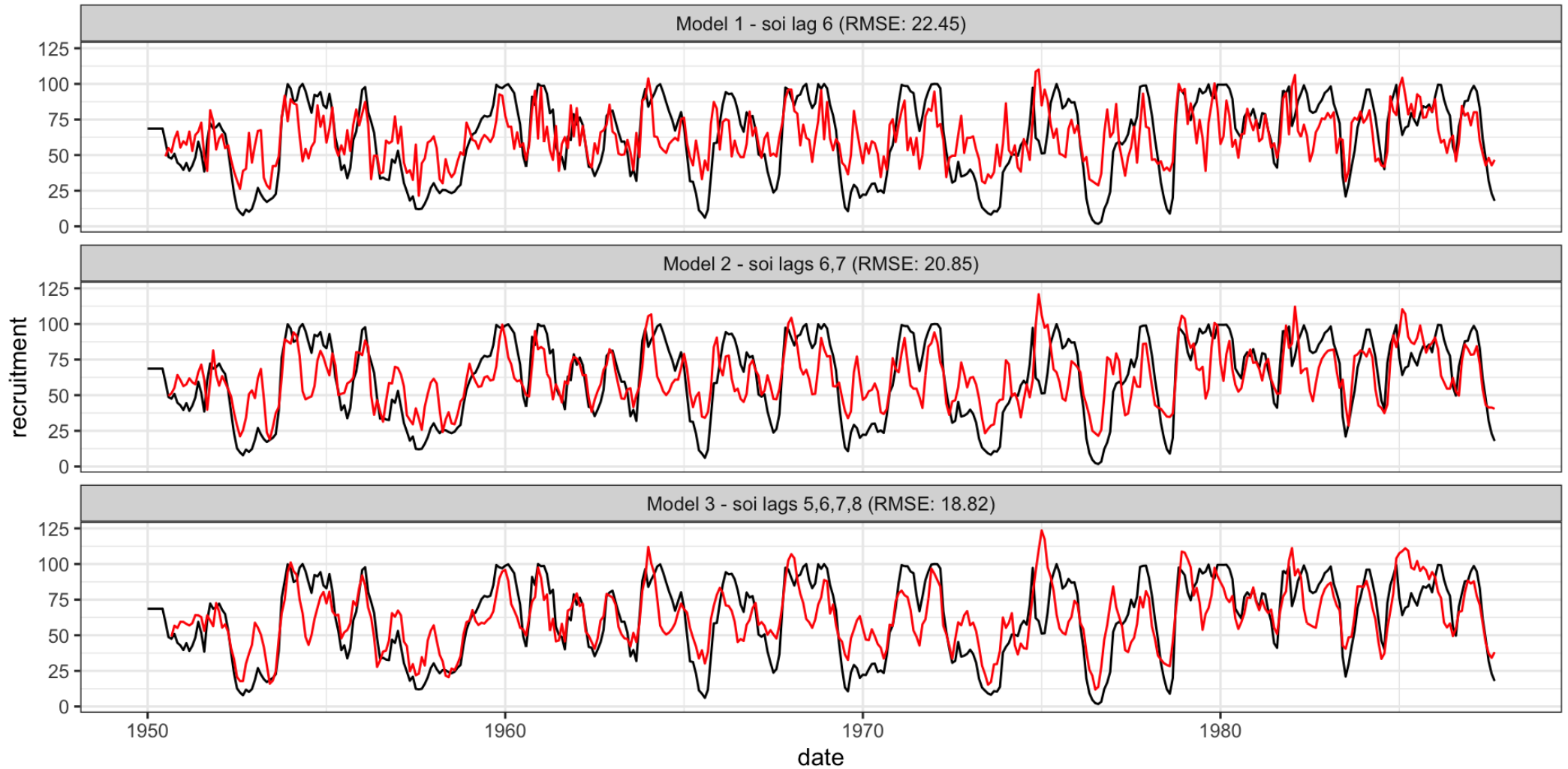
Residuals:

Min	1Q	Median	3Q	Max
-72.409	-13.527	0.191	12.851	46.040

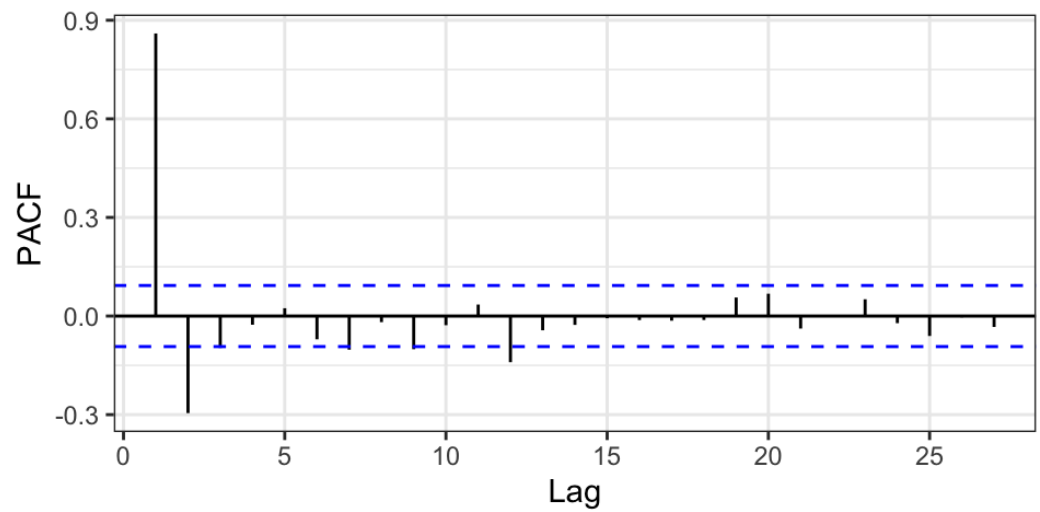
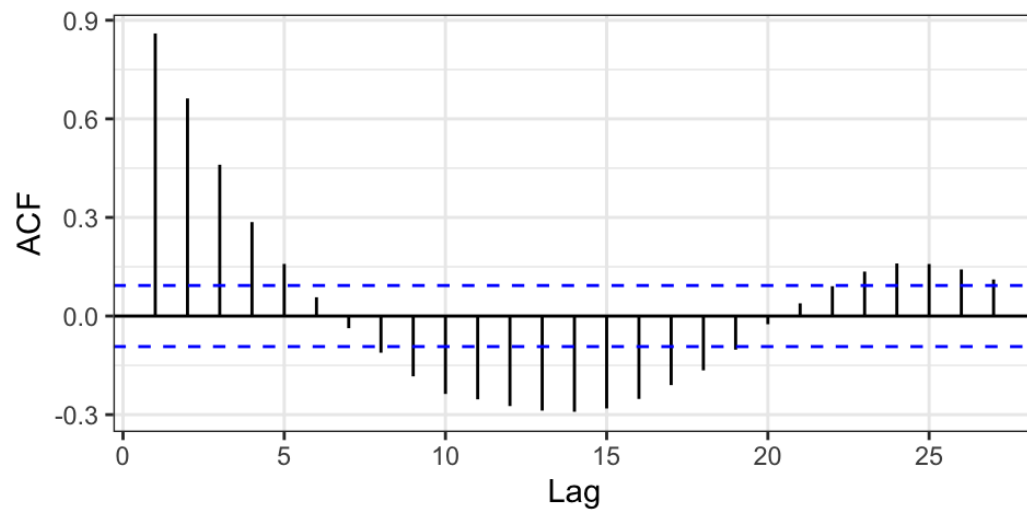
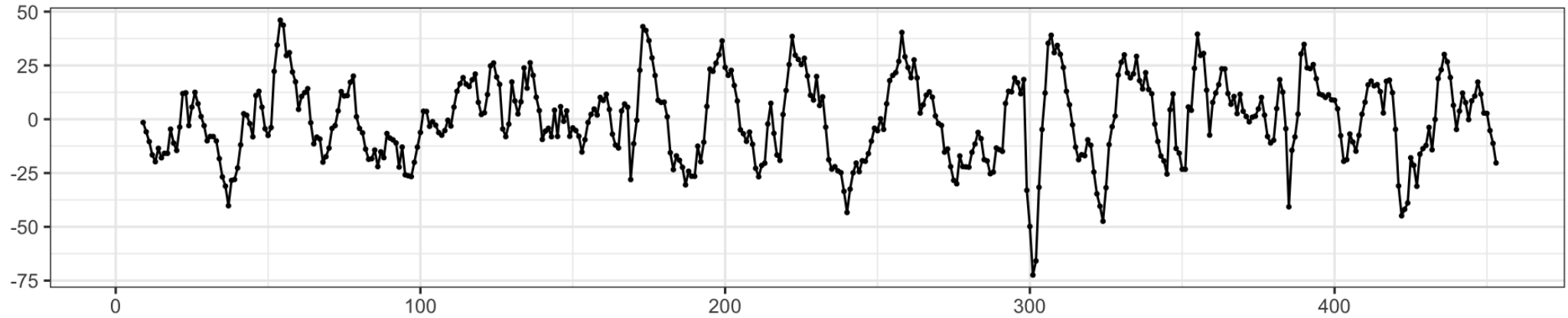
Coefficients:

	Estimate	Std. Error	t value	Pr(> t)	
(Intercept)	67.9438	0.9306	73.007	< 2e-16	***
lag(soi, 5)	-19.1502	2.9508	-6.490	2.32e-10	***
lag(soi, 6)	-15.6894	3.4334	-4.570	6.36e-06	***
lag(soi, 7)	-13.4041	3.4332	-3.904	0.000109	***
lag(soi, 8)	-23.1480	2.9530	-7.839	3.46e-14	***

Prediction



Residual ACF - Model 3



Autoregressive model 4

```
1 model4 = lm(  
2   recruitment~lag(recruitment,1) + lag(recruitment,2) +  
3       lag(soi,5)+lag(soi,6)+lag(soi,7)+lag(soi,8),  
4   data=fish  
5 )  
6 summary(model4)
```

Call:

```
lm(formula = recruitment ~ lag(recruitment, 1) + lag(recruitment,  
  2) + lag(soi, 5) + lag(soi, 6) + lag(soi, 7) + lag(soi, 8),  
  data = fish)
```

Residuals:

Min	1Q	Median	3Q	Max
-51.996	-2.892	0.103	3.117	28.579

Coefficients:

	Estimate	Std. Error	t value	Pr(> t)
(Intercept)	10.25007	1.17081	8.755	< 2e-16 ***
lag(recruitment, 1)	1.25301	0.04312	29.061	< 2e-16 ***
lag(recruitment, 2)	-0.39961	0.03998	-9.995	< 2e-16 ***
lag(soi. 5)	-20.76309	1.09906	-18.892	< 2e-16 ***

Autoregressive model 5

```
1 model5 = lm(  
2   recruitment~lag(recruitment,1) + lag(recruitment,2) +  
3       lag(soi,5) + lag(soi,6),  
4   data=fish  
5 )  
6 summary(model5)
```

Call:

```
lm(formula = recruitment ~ lag(recruitment, 1) + lag(recruitment,  
  2) + lag(soi, 5) + lag(soi, 6), data = fish)
```

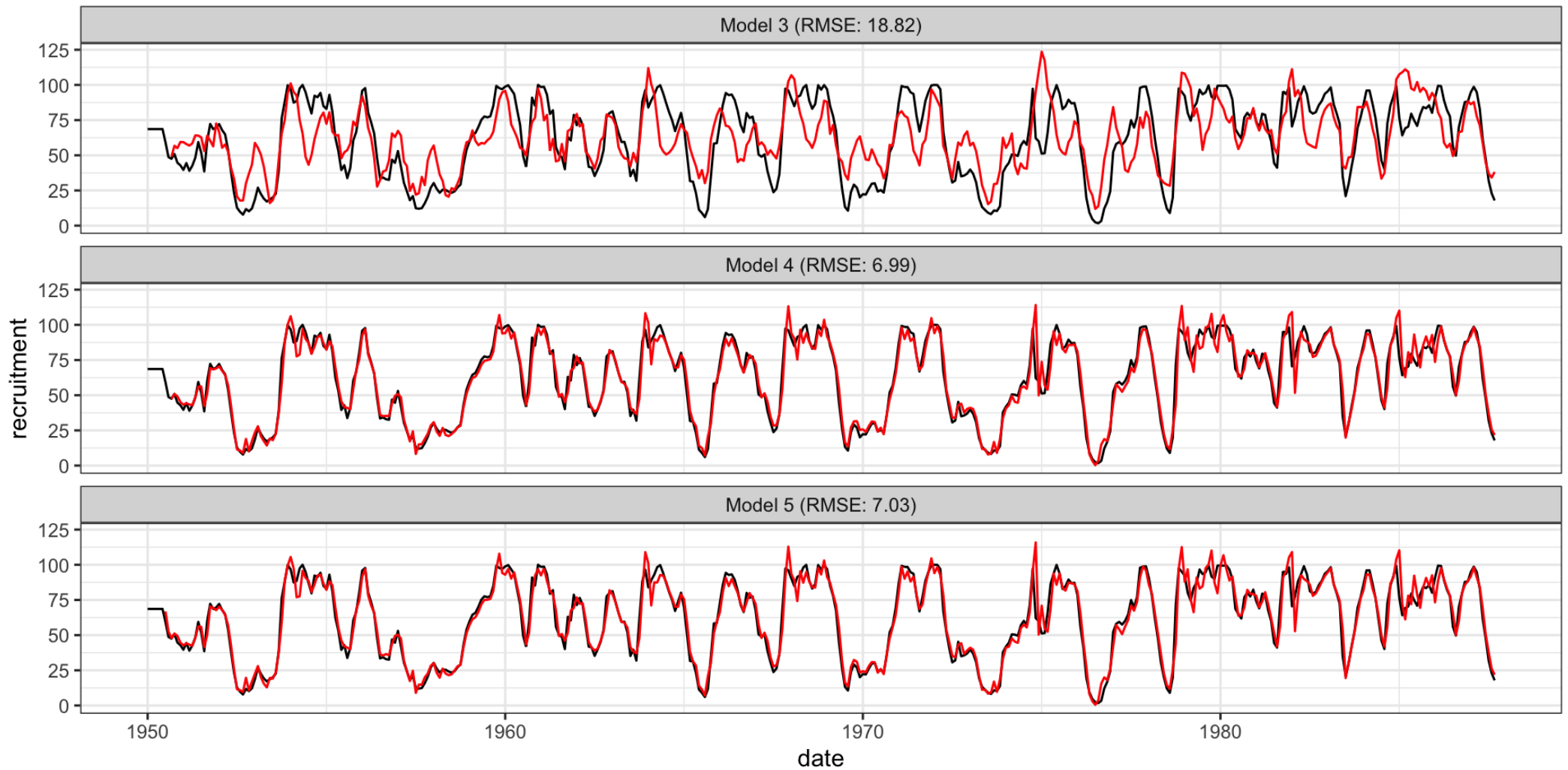
Residuals:

Min	1Q	Median	3Q	Max
-53.786	-2.999	-0.035	3.031	27.669

Coefficients:

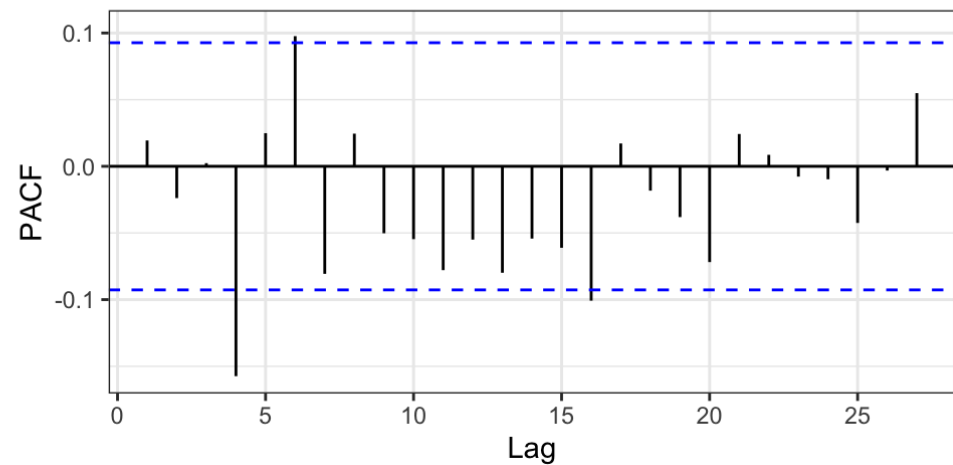
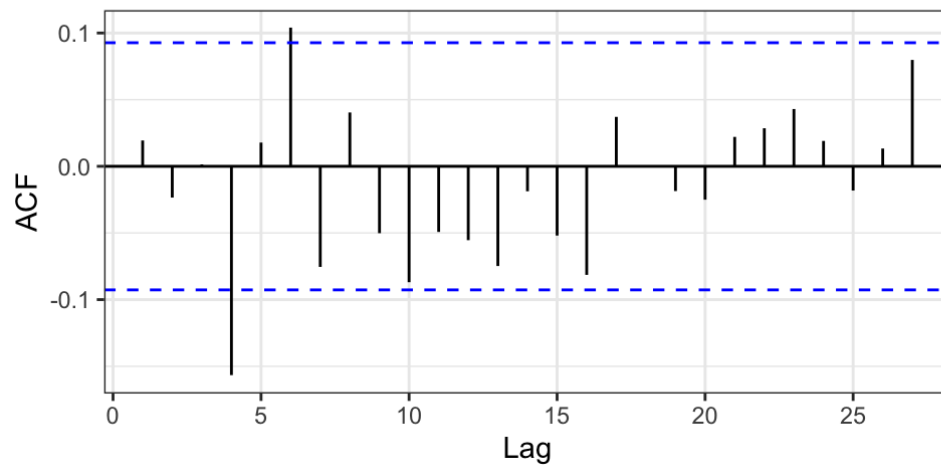
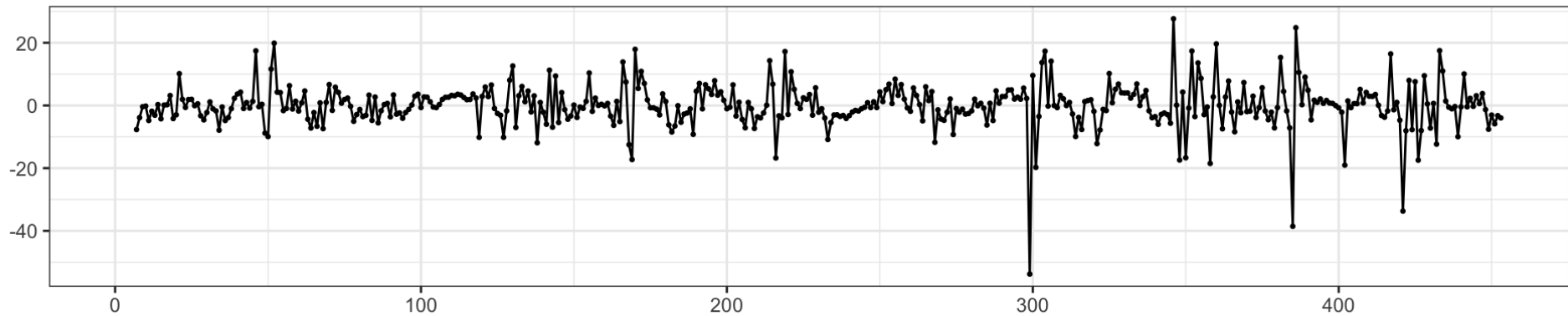
	Estimate	Std. Error	t value	Pr(> t)	
(Intercept)	8.78498	1.00171	8.770	< 2e-16	***
lag(recruitment, 1)	1.24575	0.04314	28.879	< 2e-16	***
lag(recruitment, 2)	-0.37193	0.03846	-9.670	< 2e-16	***
lag(soi, 5)	-20.83776	1.10208	-18.908	< 2e-16	***
lag(soi, 6)	8.55600	1.43146	5.977	4.68e-09	***

Prediction



Residual ACF - Model 5

```
1 broom::augment(model5, newdata=fish) %>%  
2   pull(.resid) %>%  
3   forecast::ggtsdisplay()
```



Non-stationarity

Non-stationary models

All happy families are alike; each unhappy family is unhappy in its own way.

- Tolstoy, Anna Karenina

This applies to time series models as well, just replace happy family with stationary model.

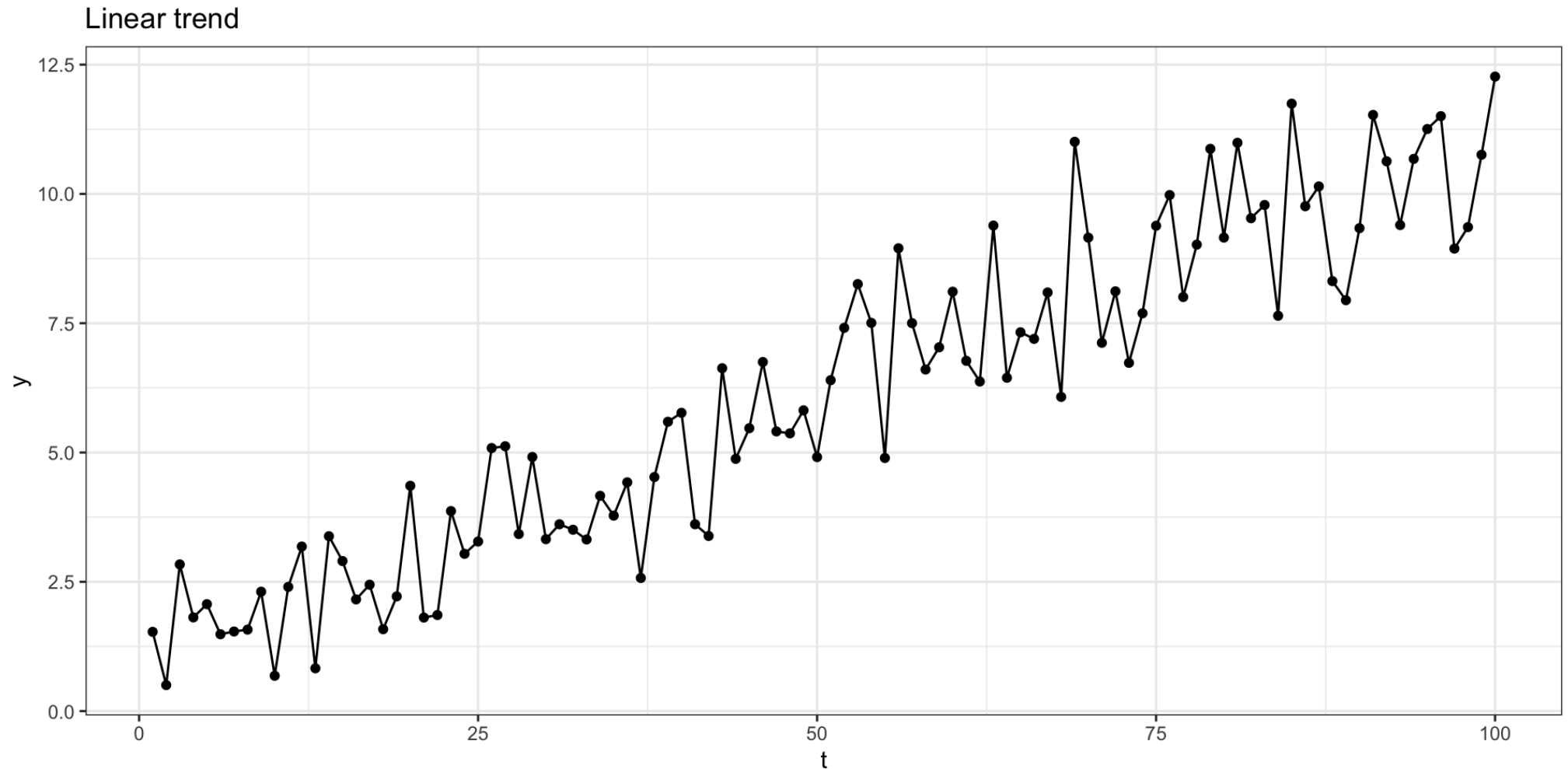
A simple example of a non-stationary time series is a trend stationary model

$$y_t = \mu(t) + w_t$$

where $\mu(t)$ denotes a time dependent trend and w_t is a white noise (stationary) process.

Linear trend model

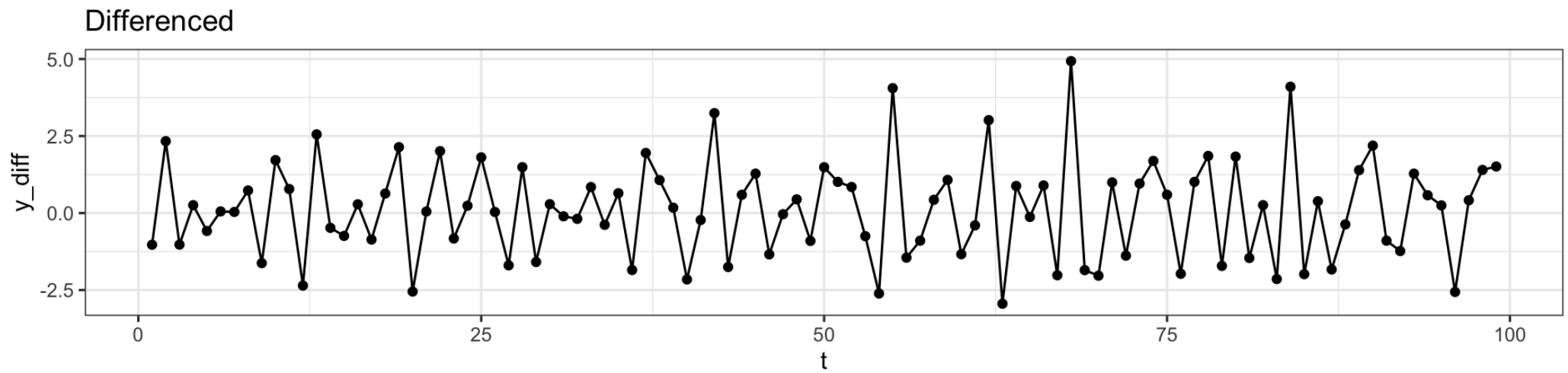
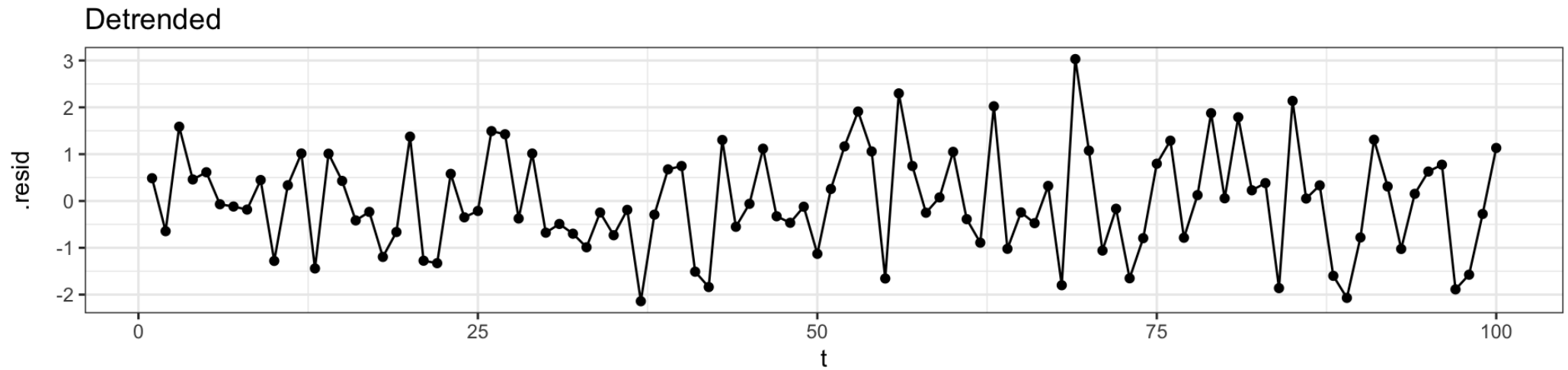
Lets imagine a simple model where $y_t = \delta + \beta t + x_t$ where δ and β are constants and x_t is a stationary process.



Differencing

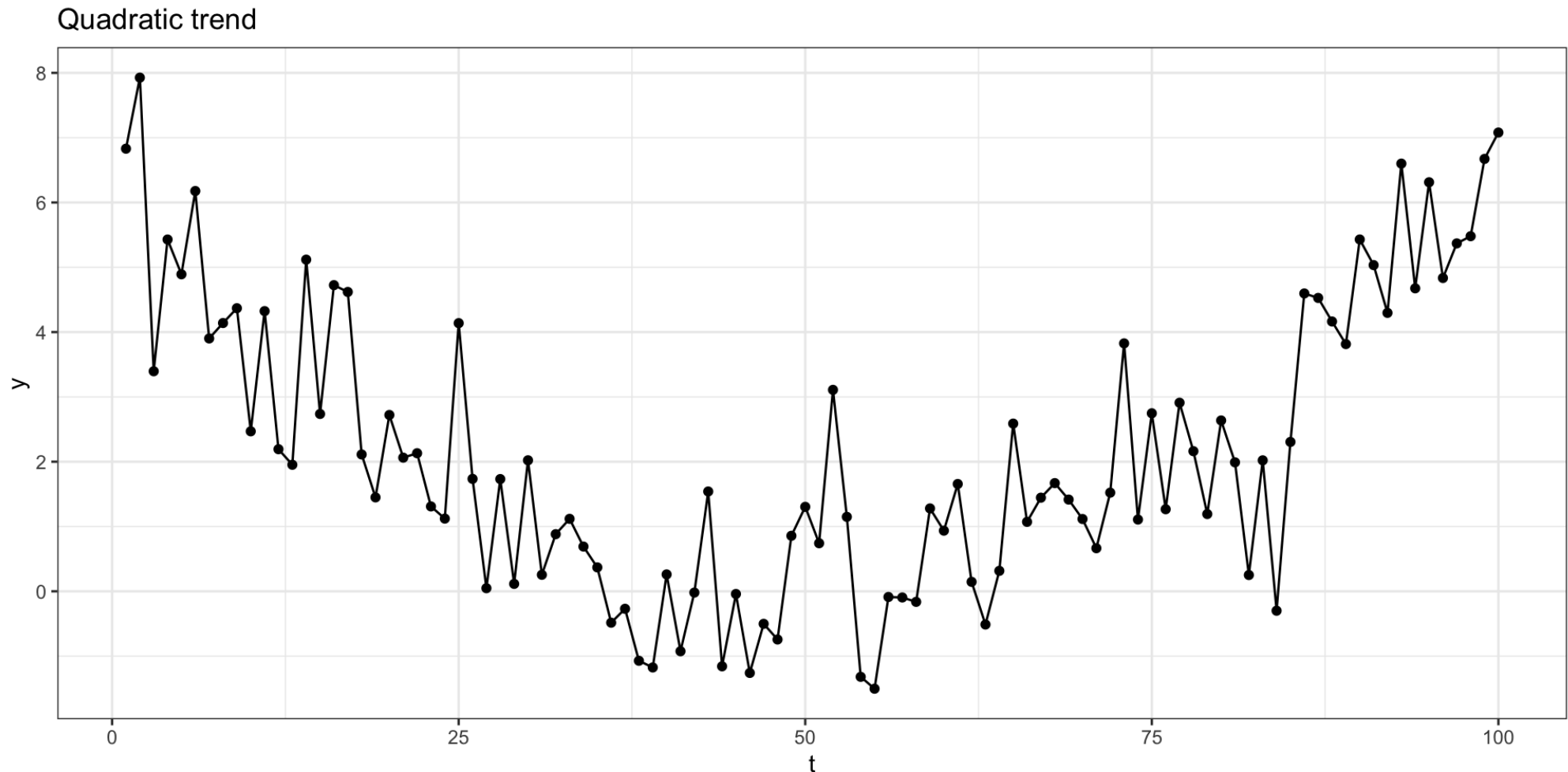
An simple approach to remove trend is to difference your response variable, specifically examine $d_t = y_t - y_{t-1}$ instead of y_t .

Detrending vs Differencing



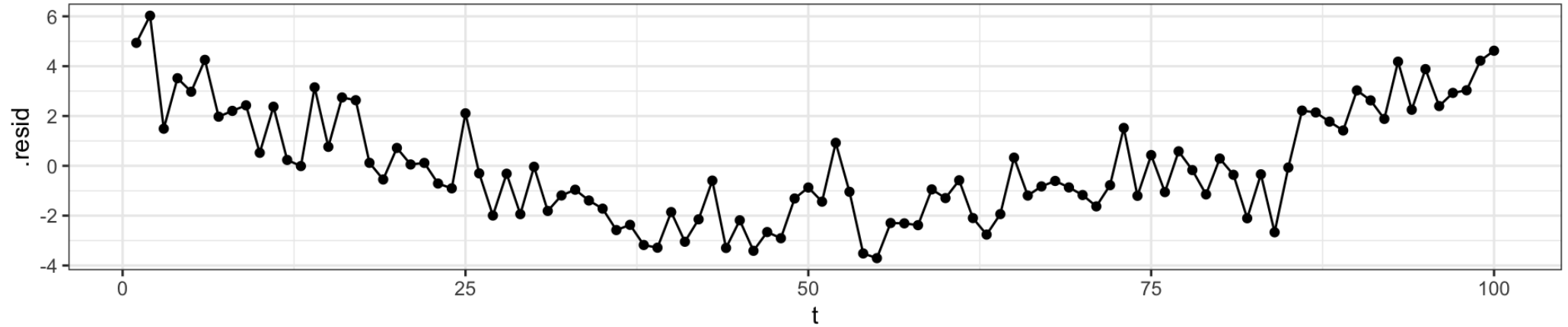
Quadratic trend model

Lets imagine another simple model where $y_t = \delta + \beta t + \gamma t^2 + x_t$ where δ , β , and γ are constants and x_t is a stationary process.

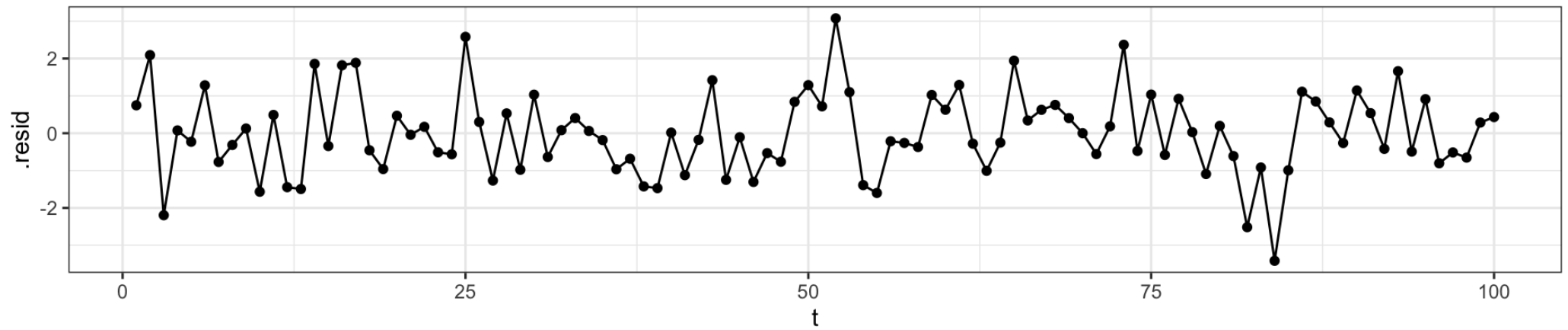


Detrending

Detrended - Linear



Detrended - Quadratic

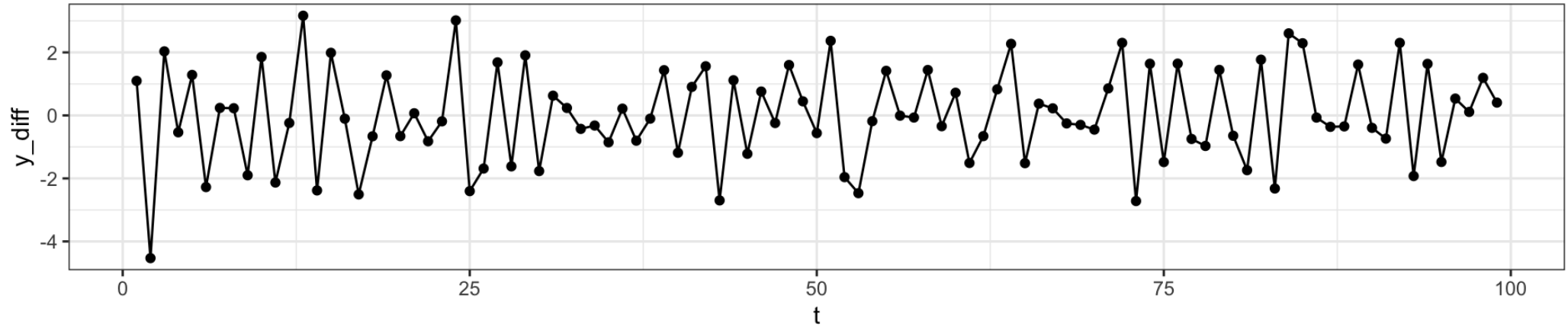


2nd order differencing

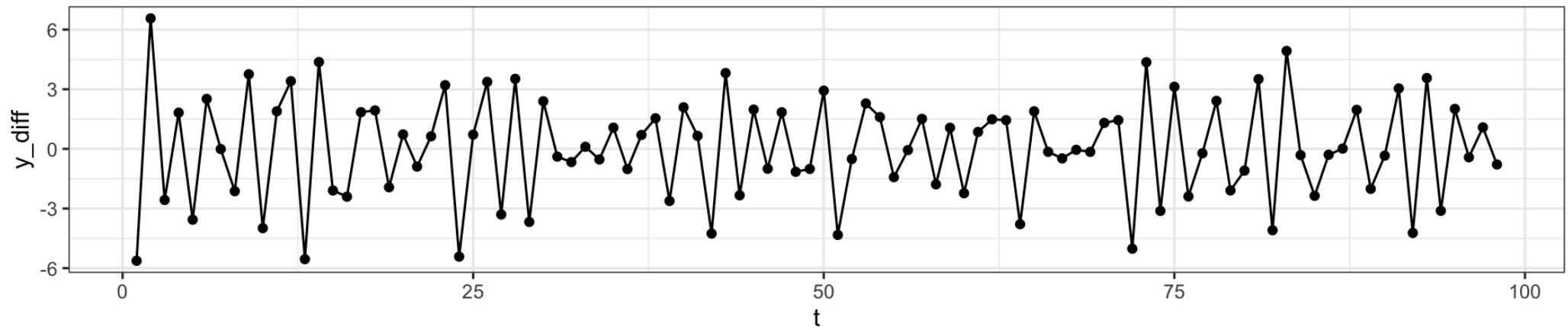
Let $d_t = y_t - y_{t-1}$ be a first order difference then $d_t - d_{t-1}$ is a 2nd order difference.

Differencing

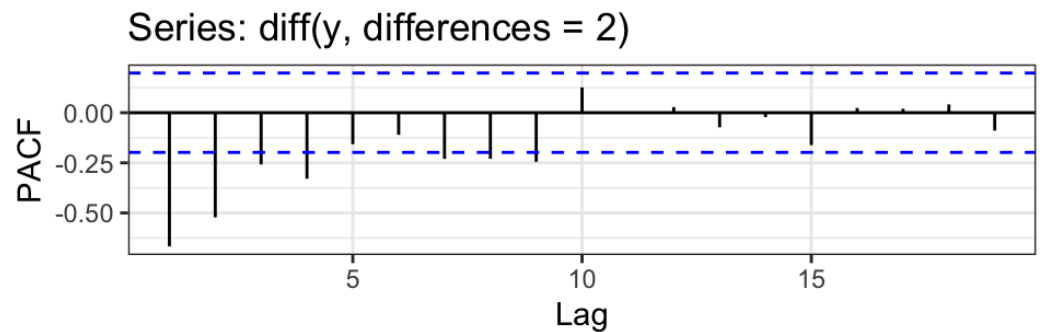
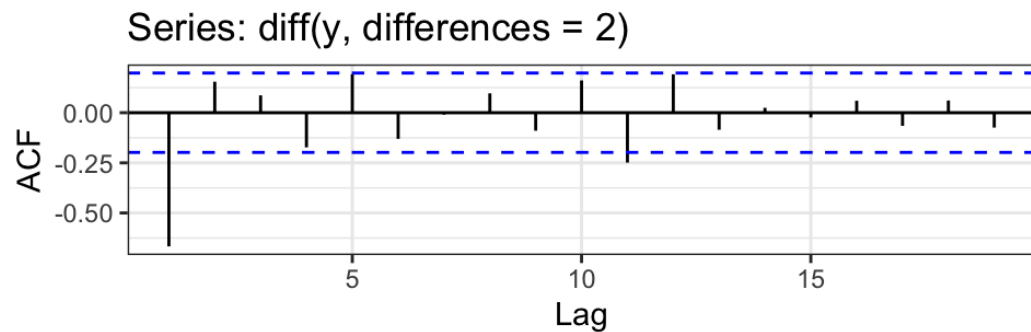
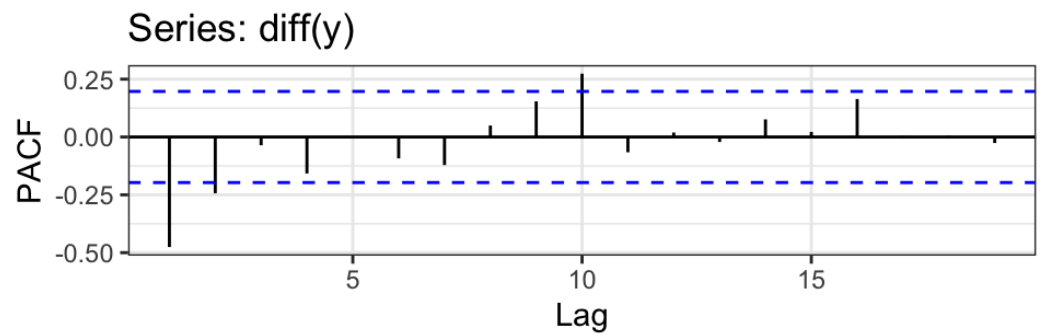
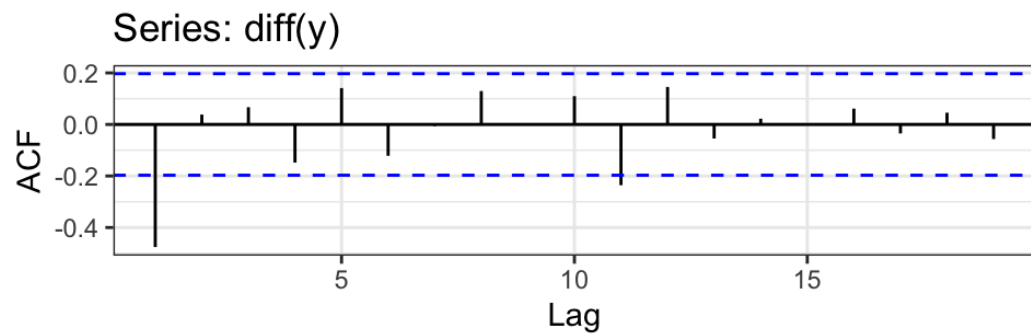
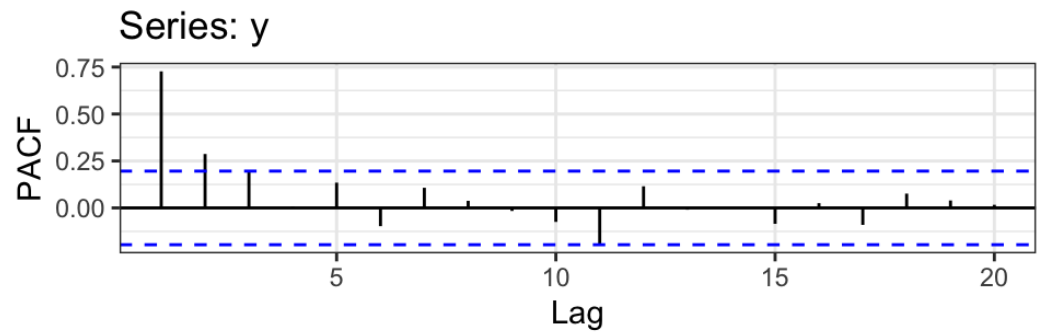
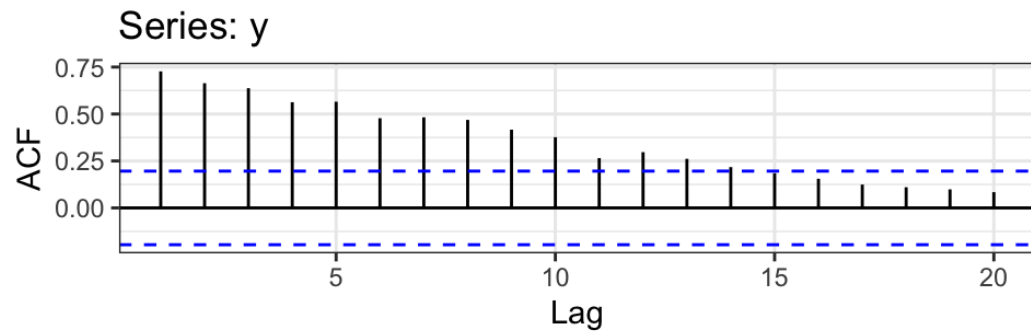
1st Difference



2nd Difference



Differencing - ACF



AR Models

AR(1)

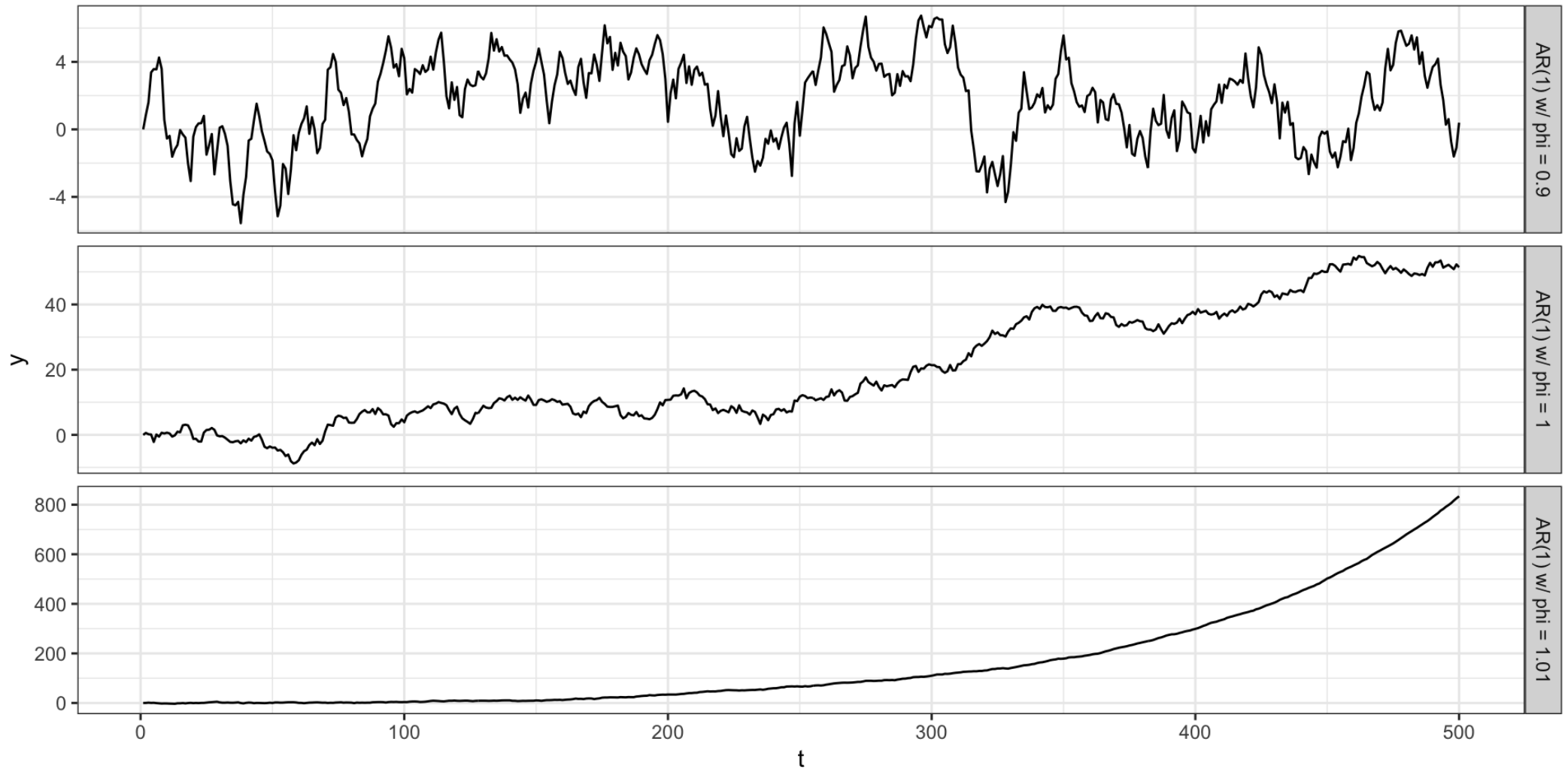
Last time we mentioned a random walk with trend process where $y_t = \delta + y_{t-1} + w_t$.

The AR(1) process is a generalization of this where we include a coefficient in front of the y_{t-1} term.

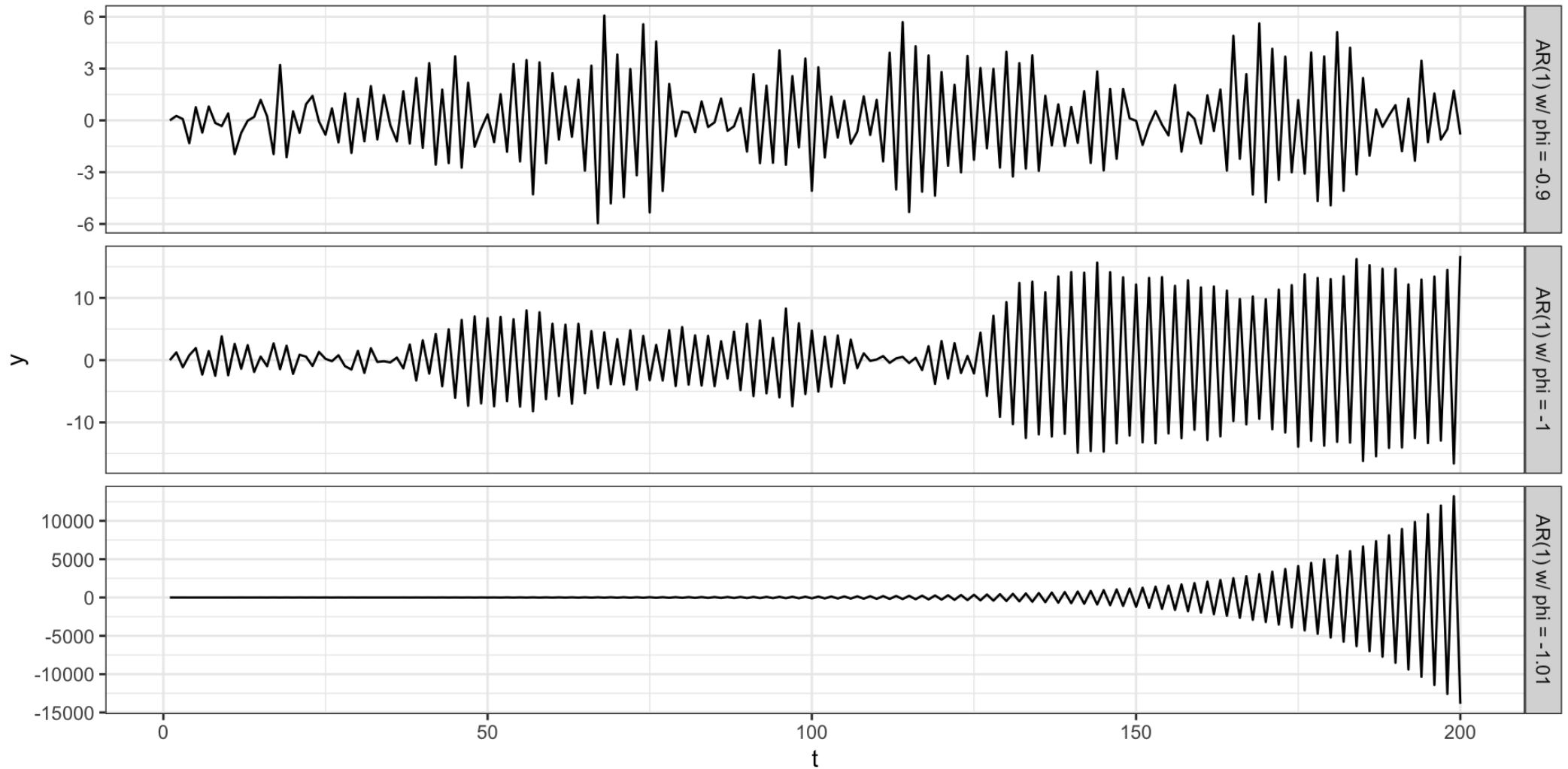
$$\text{AR(1)} : \quad y_t = \delta + \phi y_{t-1} + w_t$$

$$w_t \sim N(0, \sigma_w^2)$$

AR(1) - Positive ϕ



AR(1) - Negative ϕ



Stationarity of $AR(1)$ processes

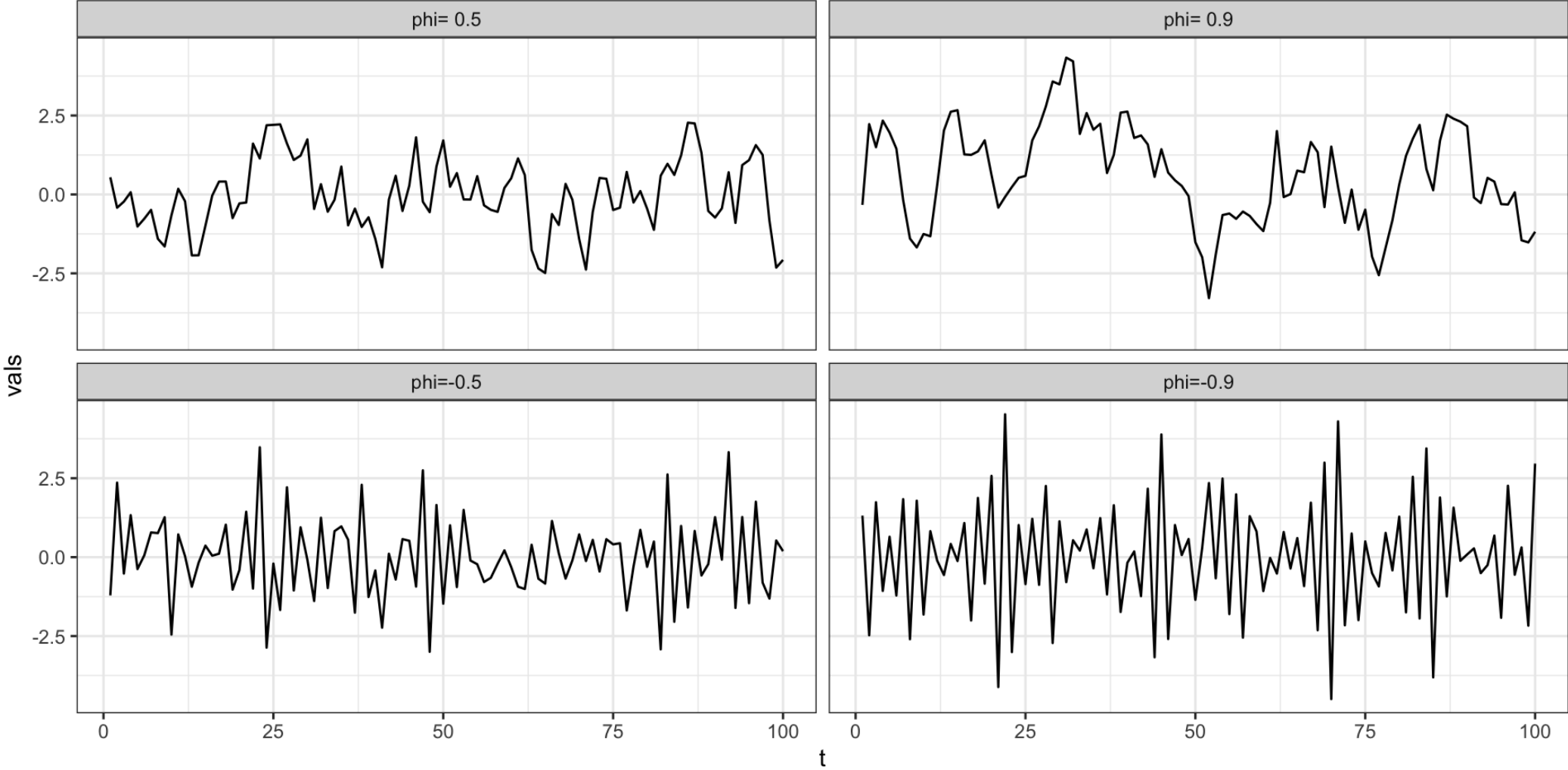
Lets rewrite the $AR(1)$ without any autoregressive terms

Stationarity of $AR(1)$ processes

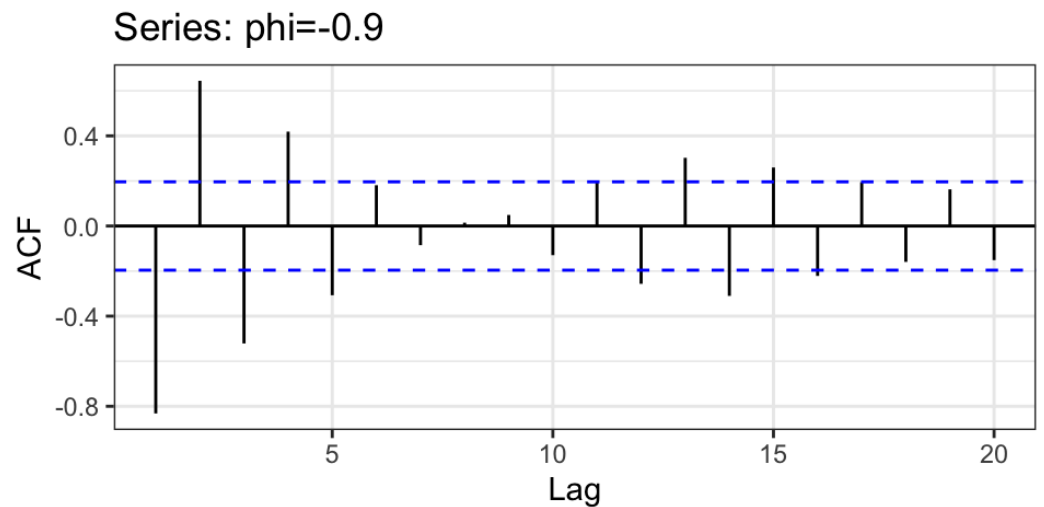
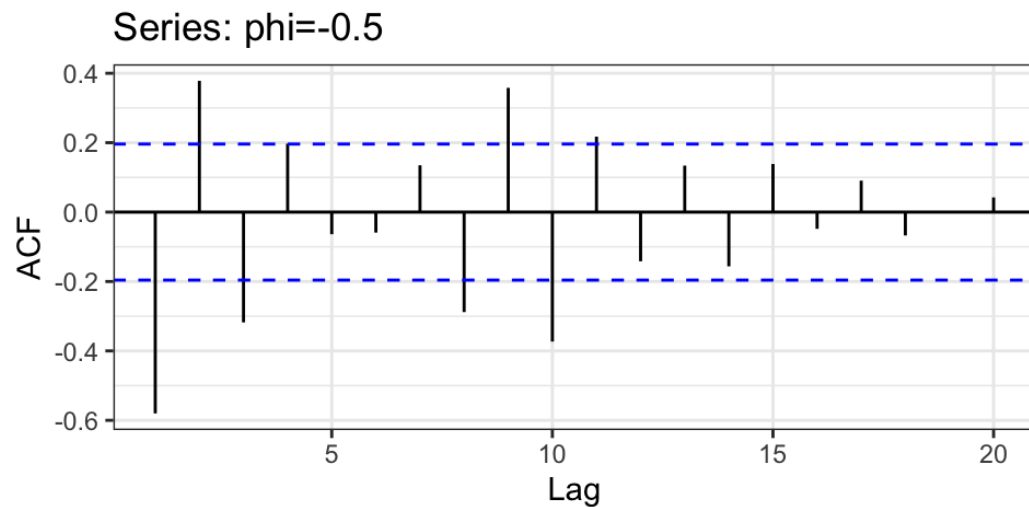
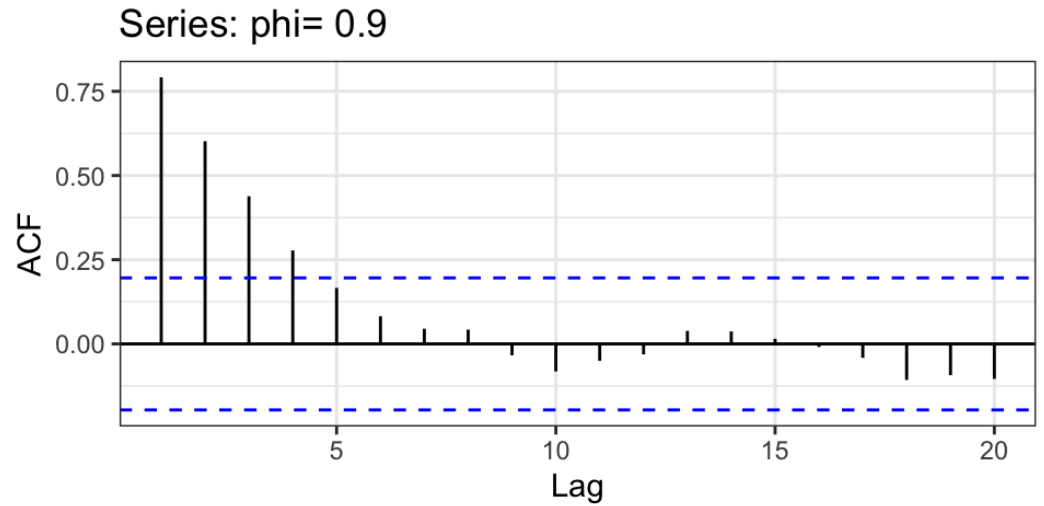
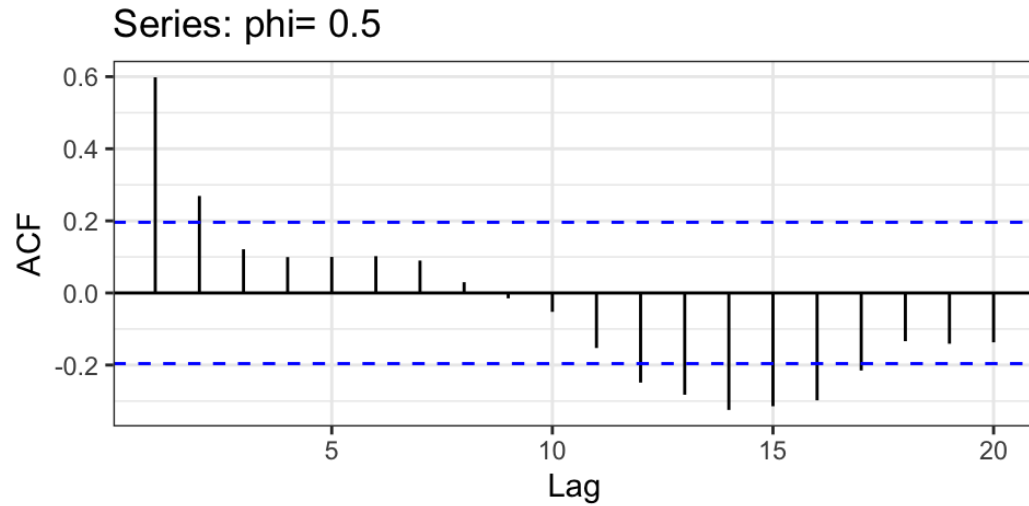
Under what conditions will an $AR(1)$ process be stationary?

Properties of a stationary $AR(1)$ process

Identifying AR(1) Processes



Identifying AR(1) Processes - ACFs



Identifying AR(1) Processes - PACFs

