

Approximating the Fisher Information for a Partially-Observable Growing Population

Ali Eshragh

(Joint work with Nigel Bean and Joshua Ross)

School of Mathematical and Physical Sciences & CARMA
The University of Newcastle, Australia

ICERM Workshop on
Challenges in 21st Century Experimental Mathematical Computation
Providence, US
July 21-25, 2014

Motivation

- **Epidemiology**

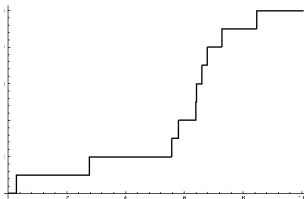


Motivation

- **Epidemiology**



- A **Growing** Population



Definition and Notation

- Let X_t denote the **population size** at time t .

Definition and Notation

- Let X_t denote the **population size** at time t .
- $\{X_t : t \in \mathbb{R}_0^+\}$ is a **stochastic process** .

Definition and Notation

- Let X_t denote the **population size** at time t .
- $\{X_t : t \in \mathbb{R}_0^+\}$ is a **stochastic process** .
- Suppose $\{X_t : t \in \mathbb{R}_0^+\}$ is a **simple birth process (SBP)** with the **birth rate** λ . Moreover, $X_0 \stackrel{a.s.}{=} x_0$.

Definition and Notation

- Let X_t denote the **population size** at time t .
- $\{X_t : t \in \mathbb{R}_0^+\}$ is a **stochastic process**.
- Suppose $\{X_t : t \in \mathbb{R}_0^+\}$ is a **simple birth process (SBP)** with the **birth rate** λ . Moreover, $X_0 \stackrel{a.s.}{=} x_0$.
- It is **Markovian**, that is

$$\Pr(X_{t_{n+1}} = x_{n+1} | X_{t_n} = x_n, \dots, X_{t_1} = x_1) = \Pr(X_{t_{n+1}} = x_{n+1} | X_{t_n} = x_n),$$

for all possible values of n and t_1, \dots, t_{n+1} .

Definition and Notation

- Let X_t denote the **population size** at time t .
- $\{X_t : t \in \mathbb{R}_0^+\}$ is a **stochastic process**.
- Suppose $\{X_t : t \in \mathbb{R}_0^+\}$ is a **simple birth process (SBP)** with the **birth rate** λ . Moreover, $X_0 \stackrel{a.s.}{=} x_0$.
- It is **Markovian**, that is

$$\Pr(X_{t_{n+1}} = x_{n+1} | X_{t_n} = x_n, \dots, X_{t_1} = x_1) = \Pr(X_{t_{n+1}} = x_{n+1} | X_{t_n} = x_n),$$

for all possible values of n and t_1, \dots, t_{n+1} .

- The **transition probability** is equal to

$$\Pr(X_{s+t} = j | X_s = i) = \binom{j-1}{i-1} e^{-\lambda t i} (1 - e^{-\lambda t})^{j-i}.$$

Likelihood Function

- **Estimating** the unknown parameter λ through **maximum likelihood** method.

Likelihood Function

- **Estimating** the unknown parameter λ through **maximum likelihood** method.
- Take the **observations** X_{t_1}, \dots, X_{t_n} at observation times $0 < t_1 \leq \dots \leq t_n \leq \tau$, respectively.

Likelihood Function

- **Estimating** the unknown parameter λ through **maximum likelihood** method.
- Take the **observations** X_{t_1}, \dots, X_{t_n} at observation times $0 < t_1 \leq \dots \leq t_n \leq \tau$, respectively.
- Construct the **likelihood function**

$$\mathcal{L}(x_1, \dots, x_n; \lambda) = \Pr(X_{t_1} = x_1, \dots, X_{t_n} = x_n | \lambda)$$

Likelihood Function

- **Estimating** the unknown parameter λ through **maximum likelihood** method.
- Take the **observations** X_{t_1}, \dots, X_{t_n} at observation times $0 < t_1 \leq \dots \leq t_n \leq \tau$, respectively.
- Construct the **likelihood function**

$$\begin{aligned}\mathcal{L}(x_1, \dots, x_n; \lambda) &= \Pr(X_{t_1} = x_1, \dots, X_{t_n} = x_n | \lambda) \\ &= \prod_{i=2}^n \Pr(X_{t_i} = x_i | X_{t_{i-1}} = x_{i-1}, \dots, X_{t_1} = x_1) \Pr(X_{t_1} = x_1)\end{aligned}$$

Likelihood Function

- **Estimating** the unknown parameter λ through **maximum likelihood** method.
- Take the **observations** X_{t_1}, \dots, X_{t_n} at observation times $0 < t_1 \leq \dots \leq t_n \leq \tau$, respectively.
- Construct the **likelihood function**

$$\begin{aligned}\mathcal{L}(x_1, \dots, x_n; \lambda) &= \Pr(X_{t_1} = x_1, \dots, X_{t_n} = x_n | \lambda) \\ &= \prod_{i=2}^n \Pr(X_{t_i} = x_i | X_{t_{i-1}} = x_{i-1}, \dots, X_{t_1} = x_1) \Pr(X_{t_1} = x_1) \\ &= \prod_{i=2}^n \Pr(X_{t_i} = x_i | X_{t_{i-1}} = x_{i-1}) \Pr(X_{t_1} = x_1)\end{aligned}$$

Likelihood Function

- **Estimating** the unknown parameter λ through **maximum likelihood** method.
- Take the **observations** X_{t_1}, \dots, X_{t_n} at observation times $0 < t_1 \leq \dots \leq t_n \leq \tau$, respectively.
- Construct the **likelihood function**

$$\begin{aligned}\mathcal{L}(x_1, \dots, x_n; \lambda) &= \Pr(X_{t_1} = x_1, \dots, X_{t_n} = x_n | \lambda) \\ &= \prod_{i=2}^n \Pr(X_{t_i} = x_i | X_{t_{i-1}} = x_{i-1}, \dots, X_{t_1} = x_1) \Pr(X_{t_1} = x_1) \\ &= \prod_{i=2}^n \Pr(X_{t_i} = x_i | X_{t_{i-1}} = x_{i-1}) \Pr(X_{t_1} = x_1) \\ &= \prod_{i=1}^n \binom{x_i - 1}{x_{i-1} - 1} e^{-\lambda(t_i - t_{i-1})x_{i-1}} (1 - e^{-\lambda(t_i - t_{i-1})})^{x_i - x_{i-1}}.\end{aligned}$$

Observation Times

- **When** should we take the observations X_{t_1}, \dots, X_{t_n} ?

Observation Times

- **When** should we take the observations X_{t_1}, \dots, X_{t_n} ?
- Presumably, a good choice is finding observation times t_1, \dots, t_n such that the **expected volume of information** obtained from these observations to estimate the unknown parameter λ is **maximized**.

Observation Times

- **When** should we take the observations X_{t_1}, \dots, X_{t_n} ?
- Presumably, a good choice is finding observation times t_1, \dots, t_n such that the **expected volume of information** obtained from these observations to estimate the unknown parameter λ is **maximized**.
- A good tool to measure the expected volume of information gained from a set of observations is the **Fisher Information**.

Observation Times

- **When** should we take the observations X_{t_1}, \dots, X_{t_n} ?
- Presumably, a good choice is finding observation times t_1, \dots, t_n such that the **expected volume of information** obtained from these observations to estimate the unknown parameter λ is **maximized**.
- A good tool to measure the expected volume of information gained from a set of observations is the **Fisher Information**.
- It can be shown that

$$\mathcal{FI}_{(X_{t_1}, \dots, X_{t_n})}(\lambda) = E_{\mathcal{L}} \left[\left(\frac{d}{d\lambda} \ln(\mathcal{L}(X_{t_1}, \dots, X_{t_n}; \lambda)) \right)^2 \right].$$

Observation Times

- **When** should we take the observations X_{t_1}, \dots, X_{t_n} ?
- Presumably, a good choice is finding observation times t_1, \dots, t_n such that the **expected volume of information** obtained from these observations to estimate the unknown parameter λ is **maximized**.
- A good tool to measure the expected volume of information gained from a set of observations is the **Fisher Information**.
- It can be shown that

$$\mathcal{FI}_{(X_{t_1}, \dots, X_{t_n})}(\lambda) = E_{\mathcal{L}} \left[\left(\frac{d}{d\lambda} \ln(\mathcal{L}(X_{t_1}, \dots, X_{t_n}; \lambda)) \right)^2 \right].$$

- Hence, $(t_1^*, \dots, t_n^*) \in \operatorname{argmax}\{\mathcal{FI}_{(X_{t_1}, \dots, X_{t_n})}(\lambda)\}$.

Fisher Information and Optimal Observation Times

Proposition (Becker and Kersting, 1983)

The **Fisher information** for a SBP with the parameter λ , the initial value of x_0 and the observation times of (t_1, \dots, t_n) is as follows:

$$\mathcal{FI}_{(X_{t_1}, \dots, X_{t_n})}(\lambda) = x_0 \sum_{i=1}^n \frac{(t_i - t_{i-1})^2}{e^{-\lambda t_{i-1}} - e^{-\lambda t_i}}.$$

Fisher Information and Optimal Observation Times

Proposition (Becker and Kersting, 1983)

The **Fisher information** for a SBP with the parameter λ , the initial value of x_0 and the observation times of (t_1, \dots, t_n) is as follows:

$$\mathcal{FI}_{(X_{t_1}, \dots, X_{t_n})}(\lambda) = x_0 \sum_{i=1}^n \frac{(t_i - t_{i-1})^2}{e^{-\lambda t_{i-1}} - e^{-\lambda t_i}}.$$

Optimal Observation Times (Becker and Kersting, 1983)

$$t_i^* \approx \frac{3}{\lambda} \log \left(1 + \frac{i}{n} (e^{\frac{\lambda \tau}{3}} - 1) \right) \quad \text{for } i = 1, \dots, n$$

Definition and Notation

- Suppose that at each observation time, we can count the population, **partially**.

Definition and Notation

- Suppose that at each observation time, we can count the population, **partially**.
- At each observation time, each individual can be counted **independently** with probability p .

Definition and Notation

- Suppose that at each observation time, we can count the population, **partially**.
- At each observation time, each individual can be counted **independently** with probability p .
- Y_t is the number of individuals observed at at time t .

Definition and Notation

- Suppose that at each observation time, we can count the population, **partially**.
- At each observation time, each individual can be counted **independently** with probability \mathbf{p} .
- \mathbf{Y}_t is the number of individuals observed at at time t .
- $(Y_t | X_t = x) \sim \text{Binomial}(x, \mathbf{p})$.

Definition and Notation

- Suppose that at each observation time, we can count the population, **partially**.
- At each observation time, each individual can be counted **independently** with probability \mathbf{p} .
- \mathbf{Y}_t is the number of individuals observed at at time t .
- $(Y_t | X_t = x) \sim \text{Binomial}(x, \mathbf{p})$.
- We call the stochastic process $\{Y_t : t \in \mathbb{R}_0^+\}$ the **partially-observable simple birth process (POSBP)** with parameters (λ, ρ) .

Definition and Notation

- Suppose that at each observation time, we can count the population, **partially**.
- At each observation time, each individual can be counted **independently** with probability \mathbf{p} .
- \mathbf{Y}_t is the number of individuals observed at at time t .
- $(Y_t | X_t = x) \sim \text{Binomial}(x, \mathbf{p})$.
- We call the stochastic process $\{Y_t : t \in \mathbb{R}_0^+\}$ the **partially-observable simple birth process (POSBP)** with parameters (λ, \mathbf{p}) .
- $\text{POSBP}(\lambda, \mathbf{1}) \equiv \text{SBP}(\lambda)$.

Markovian or non-Markovian?

Theorem (Bean, Elliott, Eshragh and Ross; 2014)

The POSBP $\{Y_t : t \in \mathbb{R}_0^+\}$ with parameters (λ, p) is **not Markovian**.

Markovian or non-Markovian?

Theorem (Bean, Elliott, Eshragh and Ross; 2014)

The POSBP $\{Y_t : t \in \mathbb{R}_0^+\}$ with parameters (λ, p) is **not Markovian**.

- However,

$$\begin{aligned} & \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n} | X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\ &= \prod_{i=1}^n \Pr(Y_{t_i} = y_{t_i} | X_{t_i} = x_{t_i}). \end{aligned}$$

Likelihood Function

- The likelihood function:

$$\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda) = \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n})$$

Likelihood Function

- The likelihood function:

$$\begin{aligned}\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda) &= \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n}) \\ &= \sum_{x_{t_1}, \dots, x_{t_n}} \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n} | X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\ &\quad \Pr(X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n})\end{aligned}$$

Likelihood Function

- The likelihood function:

$$\begin{aligned}\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda) &= \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n}) \\ &= \sum_{x_{t_1}, \dots, x_{t_n}} \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n} | X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\ &\quad \Pr(X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\ &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \Pr(Y_{t_i} = y_{t_i} | X_{t_i} = x_{t_i}) \Pr(X_{t_i} = x_{t_i} | X_{t_{i-1}} = x_{t_{i-1}})\end{aligned}$$

Likelihood Function

- The likelihood function:

$$\begin{aligned}
 \mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda) &= \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n} | X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\
 &\quad \Pr(X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \Pr(Y_{t_i} = y_{t_i} | X_{t_i} = x_{t_i}) \Pr(X_{t_i} = x_{t_i} | X_{t_{i-1}} = x_{t_{i-1}}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n
 \end{aligned}$$

Likelihood Function

- The likelihood function:

$$\begin{aligned}\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda) &= \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n}) \\ &= \sum_{x_{t_1}, \dots, x_{t_n}} \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n} | X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\ &\quad \Pr(X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\ &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \Pr(Y_{t_i} = y_{t_i} | X_{t_i} = x_{t_i}) \Pr(X_{t_i} = x_{t_i} | X_{t_{i-1}} = x_{t_{i-1}}) \\ &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \binom{x_{t_i}}{y_{t_i}} p^{y_{t_i}} q^{x_{t_i} - y_{t_i}}\end{aligned}$$

Likelihood Function

- The likelihood function:

$$\begin{aligned}
 \mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda) &= \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n} | X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\
 &\quad \Pr(X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \Pr(Y_{t_i} = y_{t_i} | X_{t_i} = x_{t_i}) \Pr(X_{t_i} = x_{t_i} | X_{t_{i-1}} = x_{t_{i-1}}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \binom{x_{t_i}}{y_{t_i}} p^{y_{t_i}} q^{x_{t_i} - y_{t_i}} \binom{x_{t_i} - 1}{x_{t_{i-1}} - 1} v_{i-1, i}^{x_{t_i} - 1} (1 - v_{i-1, i})^{x_{t_i} - x_{t_{i-1}}},
 \end{aligned}$$

Likelihood Function

- The likelihood function:

$$\begin{aligned}
 \mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda) &= \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \Pr(Y_{t_1} = y_{t_1}, \dots, Y_{t_n} = y_{t_n} | X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\
 &\quad \Pr(X_{t_1} = x_{t_1}, \dots, X_{t_n} = x_{t_n}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \Pr(Y_{t_i} = y_{t_i} | X_{t_i} = x_{t_i}) \Pr(X_{t_i} = x_{t_i} | X_{t_{i-1}} = x_{t_{i-1}}) \\
 &= \sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \binom{x_{t_i}}{y_{t_i}} p^{y_{t_i}} q^{x_{t_i} - y_{t_i}} \binom{x_{t_i} - 1}{x_{t_{i-1}} - 1} v_{i-1, i}^{x_{t_i} - 1} (1 - v_{i-1, i})^{x_{t_i} - x_{t_{i-1}}},
 \end{aligned}$$

where $q := 1 - p$ and $v_{i-1, i} := e^{-\lambda(t_i - t_{i-1})}$.

Theoretical Result

Proposition (Bean, Eshragh and Ross; 2014)

For a POSBP with n observations and time horizon τ , the FI is an **increasing** function of t_n . Hence, the **optimal observation time** for the last observation, that is t_n^* , is equal to τ .

Theoretical Result

Proposition (Bean, Eshragh and Ross; 2014)

For a POSBP with n observations and time horizon τ , the FI is an **increasing** function of t_n . Hence, the **optimal observation time** for the last observation, that is t_n^* , is equal to τ .

Proposition (Bean, Eshragh and Ross; 2014)

If t_1^*, \dots, t_n^* are optimal observation times for a POSBP with parameters (λ, ρ) and time-horizon τ , then $\frac{t_1^*}{\tau}, \dots, \frac{t_n^*}{\tau}$ are **optimal observation times** for a POSBP with parameters $(\lambda\tau, \rho)$ and time-horizon **1**.

Truncated Summation

- The Fisher Information:

$$\mathcal{FI}_{(Y_{t_1}, \dots, Y_{t_n})}(\lambda) = \sum_{y_{t_1}, \dots, y_{t_n}} \frac{\left(\frac{d\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda)}{d\lambda} \right)^2}{\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda)}.$$

Truncated Summation

- The Fisher Information:

$$\mathcal{FI}_{(Y_{t_1}, \dots, Y_{t_n})}(\lambda) = \sum_{y_{t_1}, \dots, y_{t_n}} \frac{\left(\frac{d\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda)}{d\lambda} \right)^2}{\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda)}.$$

- Here, the likelihood function $\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda)$ is equal to

$$\sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \binom{x_{t_i}}{y_{t_i}} p^{y_{t_i}} (1-p)^{x_{t_i}-y_{t_i}} \binom{x_{t_i}-1}{x_{t_{i-1}}-1} v_{i-1,i}^{x_{t_{i-1}}} (1-v_{i-1,i})^{x_{t_i}-x_{t_{i-1}}},$$

where $v_{i-1,i} := e^{-\lambda(t_i-t_{i-1})}$.

Truncated Summation

- The Fisher Information:

$$\mathcal{FI}_{(Y_{t_1}, \dots, Y_{t_n})}(\lambda) = \sum_{y_{t_1}, \dots, y_{t_n}} \frac{\left(\frac{d\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda)}{d\lambda} \right)^2}{\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda)}.$$

- Here, the likelihood function $\mathcal{L}(y_{t_1}, \dots, y_{t_n}; \lambda)$ is equal to

$$\sum_{x_{t_1}, \dots, x_{t_n}} \prod_{i=1}^n \binom{x_{t_i}}{y_{t_i}} p^{y_i} (1-p)^{x_{t_i}-y_i} \binom{x_{t_i}-1}{x_{t_{i-1}}-1} v_{i-1,i}^{x_{t_{i-1}}} (1-v_{i-1,i})^{x_{t_i}-x_{t_{i-1}}},$$

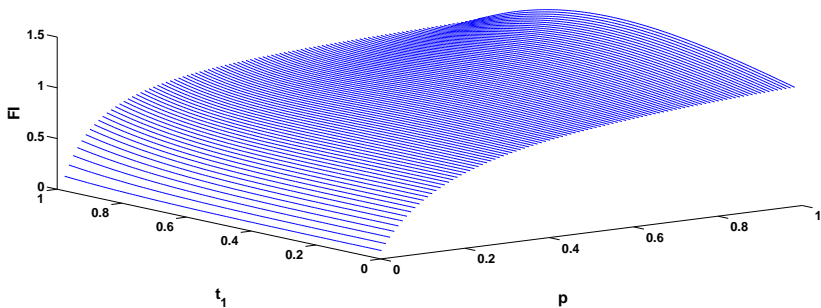
where $v_{i-1,i} := e^{-\lambda(t_i-t_{i-1})}$.

- By exploiting **Chebyshev's inequality**, we have

$$\begin{aligned} \Pr \left(E[Z] - 12\sqrt{\text{Var}(Z)} \leq Z \leq E[Z] + 12\sqrt{\text{Var}(Z)} \right) &\geq 1 - \frac{1}{12^2} \\ &= 99.3\%. \end{aligned}$$

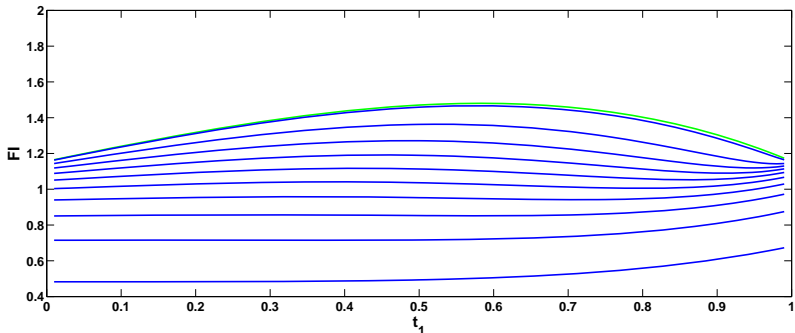
Results for $\lambda = 2$, $n = 2$ and $t_2^* = \tau = 1$

- Fisher Information vs. t_1 and p



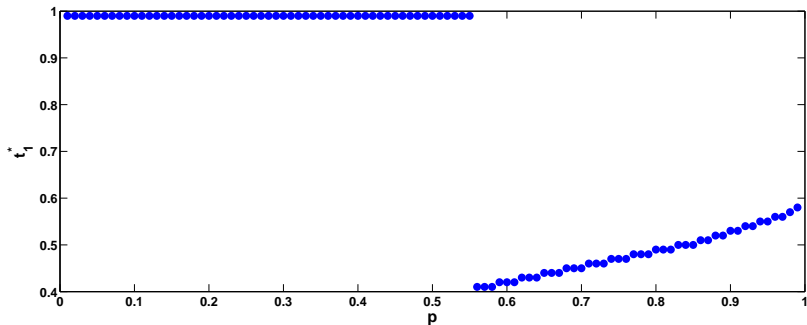
Results for $\lambda = 2$, $n = 2$ and $t_2^* = \tau = 1$

- The Fisher Information vs. t_1



Results for $\lambda = 2$, $n = 2$ and $t_2^* = \tau = 1$

- Optimal observation time t_1^* vs. p



The Chain Rule

- The likelihood function

$$\mathcal{L}(y_{t_1}, y_{t_2} | \lambda) = \Pr(Y_{t_2} = y_{t_2} | Y_{t_1} = y_{t_1}, \lambda) \Pr(Y_{t_1} = y_{t_1} | \lambda).$$

The Chain Rule

- The likelihood function

$$\mathcal{L}(y_{t_1}, y_{t_2} | \lambda) = \Pr(Y_{t_2} = y_{t_2} | Y_{t_1} = y_{t_1}, \lambda) \Pr(Y_{t_1} = y_{t_1} | \lambda).$$

- Accordingly,

$$\begin{aligned} \log(\mathcal{L}(y_{t_1}, y_{t_2} | \lambda)) &= \log(\Pr(Y_{t_2} = y_{t_2} | Y_{t_1} = y_{t_1}, \lambda)) \\ &\quad + \log(\Pr(Y_{t_1} = y_{t_1} | \lambda)). \end{aligned}$$

The Chain Rule

- The likelihood function

$$\mathcal{L}(y_{t_1}, y_{t_2} | \lambda) = \Pr(Y_{t_2} = y_{t_2} | Y_{t_1} = y_{t_1}, \lambda) \Pr(Y_{t_1} = y_{t_1} | \lambda).$$

- Accordingly,

$$\begin{aligned} \log(\mathcal{L}(y_{t_1}, y_{t_2} | \lambda)) &= \log(\Pr(Y_{t_2} = y_{t_2} | Y_{t_1} = y_{t_1}, \lambda)) \\ &\quad + \log(\Pr(Y_{t_1} = y_{t_1} | \lambda)). \end{aligned}$$

- The Fisher Information:

$$\mathcal{FI}_{(Y_{t_1}, Y_{t_2})}(\lambda) = \mathcal{FI}_{(Y_{t_2} | Y_{t_1})}(\lambda) + \mathcal{FI}_{(Y_{t_1})}(\lambda).$$

Two-Parameter Geometric Distribution

Definition

A discrete random variable V has the “**Two-Parameter Geometric**” distribution with parameters $\alpha \in [0, 1)$ and $\beta \in (0, 1)$, denoted by **TPG**(α, β), if its **probability mass function** (p.m.f.) is

$$P_V(v) = \begin{cases} \alpha & \text{for } v = 0 \\ (1 - \alpha)\beta(1 - \beta)^{v-1} & \text{for } v = 1, 2, \dots \end{cases}$$

Three-Parameter Negative Binomial Distribution

Definition

Suppose V_1, \dots, V_r are **i.i.d.** random variables with common $\text{TPG}(\alpha, \beta)$ distribution. If $\mathbf{W} := \sum_{i=1}^r \mathbf{V}_i$, then W has “**Three-Parameter Negative Binomial**” distribution with parameters \mathbf{r} , α and β , denoted by **TPNB**(\mathbf{r} , α , β).

Three-Parameter Negative Binomial Distribution

Definition

Suppose V_1, \dots, V_r are **i.i.d.** random variables with common $\text{TPG}(\alpha, \beta)$ distribution. If $\mathbf{W} := \sum_{i=1}^r \mathbf{V}_i$, then W has "**Three-Parameter Negative Binomial**" distribution with parameters r , α and β , denoted by $\text{TPNB}(r, \alpha, \beta)$.

Proposition (Bean, Eshragh and Ross; 2014)

If W follows the $\text{TPNB}(r, \alpha, \beta)$ distribution, then its **p.m.f.** is

$$P_W(w) = \begin{cases} \alpha^r & \text{for } w = 0 \\ \sum_{\xi=1}^{\min\{r, w\}} \binom{w-1}{\xi-1} \beta^\xi (1-\beta)^{w-\xi} \binom{r}{\xi} (1-\alpha)^\xi \alpha^{r-\xi} & \text{for } w \geq 1 \end{cases}$$

The Distribution of Y_t

Theorem (Bean, Eshragh and Ross; 2014)

Consider the **POSBP** $\{Y_t, t \geq 0\}$ with **parameters** (λ, p) and the **initial population size** $x_0 \geq 1$. For any real value $t > 0$, the random variable Y_t follows the **TPNB** $(x_0, (1 - p)\beta_t, \beta_t)$ distribution where

$$\beta_t := \frac{e^{-\lambda t}}{p + (1 - p)e^{-\lambda t}}.$$

The Fisher Information for a Single Observation

Proposition (Bean, Eshragh and Ross; 2014)

Consider the **POSBP** $\{Y_t, t \geq 0\}$ with **parameters** (λ, p) . The Fisher Information of a single observation Y_{t_1} for parameter λ is equal to

$$\mathcal{FI}_{Y_1}(\lambda) = \frac{pt_1^2 (p + (1-p)(1 - e^{-\lambda t_1})e^{-\lambda t_1})}{(1 - e^{-\lambda t_1})(p + (1-p)e^{-\lambda t_1})^2}.$$

The Distribution of $(Y_2|Y_1 = y_{t_1})$

Theorem (Bean, Eshragh and Ross; 2014)

Consider the **POSBP** $\{Y_t, t \geq 0\}$ with **parameters** (λ, p) . Then

$$W \stackrel{d}{=} (Y_{t_2}|Y_{t_1} = y_{t_1}) + V$$

where $(Y_{t_2}|Y_{t_1} = y_{t_1})$ and V are mutually independent and

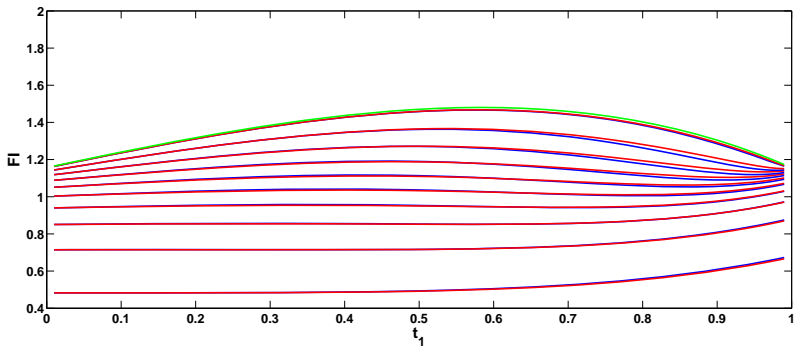
$$W \sim \text{TPNB}(y_{t_1} + 1, (1 - p)\beta^\circ, \beta^\circ)$$

and

$$V \sim \text{TPG}((1 - p)\beta_{t_2-t_1}, \beta_{t_2-t_1}).$$

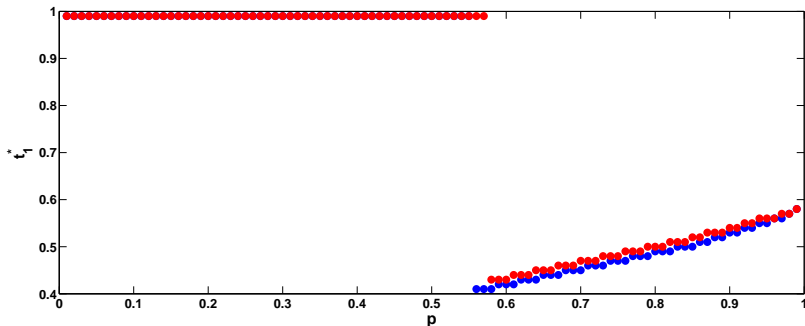
Results for $\lambda = 2$, $n = 2$ and $t_2^* = \tau = 1$

- The Fisher Information (blue) and its Approximation (red) vs. t_1



Results for $\lambda = 2$, $n = 2$ and $t_2^* = \tau = 1$

- Optimal observation time t_1^* vs. p



Bounds for the Fisher Information

- By exploiting the last two theorems, we found a **lower** and an **upper** bounds for the Fisher Information.

Bounds for the Fisher Information

- By exploiting the last two theorems, we found a **lower** and an **upper** bounds for the Fisher Information.

Theorem (Bean, Eshragh and Ross; 2014)

*The approximation function for the Fisher Information **lies within** the lower and upper bounds found for the Fisher Information.*

Bounds for the Fisher Information

- By exploiting the last two theorems, we found a **lower** and an **upper** bounds for the Fisher Information.

Theorem (Bean, Eshragh and Ross; 2014)

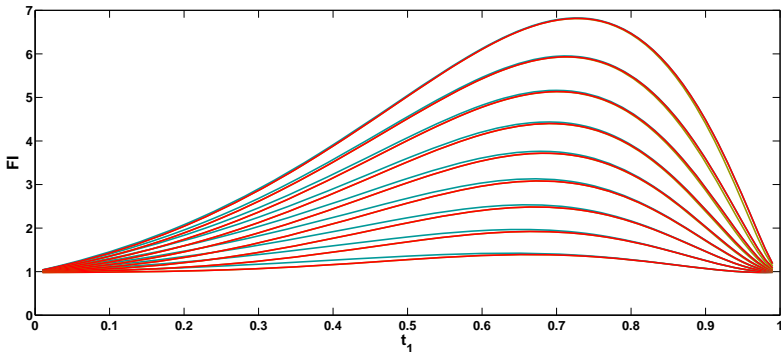
*The approximation function for the Fisher Information **lies within** the lower and upper bounds found for the Fisher Information.*

Theorem (Bean, Eshragh and Ross; 2014)

*The lower and upper bounds for the Fisher Information **approach together** as λ tends to infinity.*

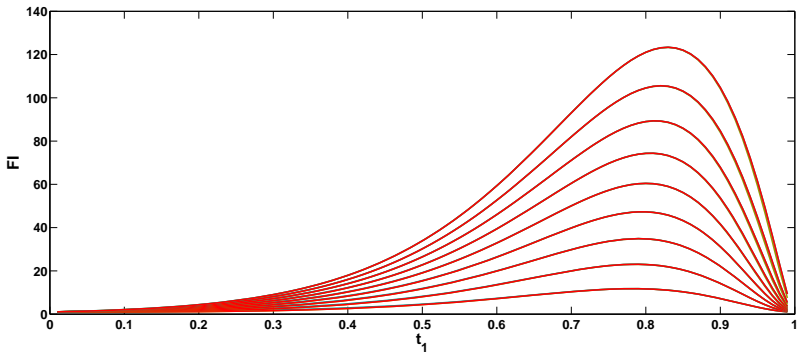
Results for $\lambda = 6$, $n = 2$ and $t_2^* = 1$

- Lower (brown) and Upper (green) Bounds for The Fisher Information and its Approximation (red) vs. t_1



Results for $\lambda = 10$, $n = 2$ and $t_2^* = 1$

- Lower (brown) and Upper (green) Bounds for The Fisher Information and its Approximation (red) vs. t_1



Further Developments

- Developing analogous approximation for **higher values** of n .

Further Developments

- Developing analogous approximation for **higher values** of n .
- Finding the Fisher Information to estimate parameter \mathbf{p} along with λ , both together.

End

Thank you ... Questions?