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Title	Orthogonal Gaussian process models
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1 respect to the mean function.

2 The idea of making the random field orthogonal to the mean function to avoid identifia-
3 bility problems was proposed in Reich et al. (2006) in the context of spatial random effects
4 modeling. Hodges and Reich (2010) used $m(x) = \beta_0 + \beta_1 x$, for modeling stomach cancer
5 incidence ratio in Slovenia with respect to the socioeconomic scores (x). Their approach
6 achieves orthogonality only at the observed locations, which induces two negatives: (i) the
7 stochastic model has a dependency on the observed locations and (ii) outside of the ob-
8 served locations, such as prediction points, there is no orthogonality. Examples in this work
9 in the spatial statistics literature include Hughes and Haran (2013) and Hanks et al. (2015).
10 Hanks et al. (2015) proposed to make the random field orthogonal to the fixed effects over
11 the entire region X , using “conditioning by Kriging” (Rue and Held (2005)). Ultimately,
12 they were forced to resort to approximation methods requiring the orthogonality condition
13 to be met only at the observed locations. We show that by carefully choosing a covariance
14 function we can make the random field orthogonal to the mean function over the entire re-
15 gion X . The proposed orthogonal Gaussian process is orthogonal to the mean function. Our
16 approach is computationally tractable and is amenable to both the frequentist and Bayesian
17 frameworks.

18 2 Orthogonal Gaussian process models

19 This section discusses the specification of an orthogonal Gaussian process $z_*(\cdot)$ in general.

20 The procedure is as follows: given a covariance function $c(\cdot, \cdot)$, replace it with the covariance

