

Lecture

On-Line Bayesian Tracking

EE 565: Position, Navigation, and Timing

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Objective

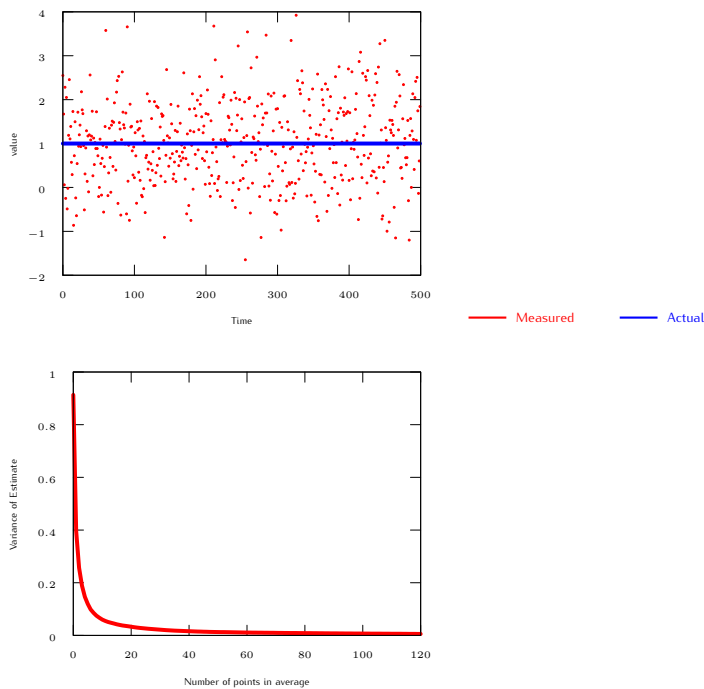
Sequentially estimate on-line the states of a system as it changes over time using observations that are corrupted with noise.

- *Filtering*: the time of the estimate coincides with the last measurement.
- *Smoothing*: the time of the estimate is within the span of the measurements.
- *Prediction*: the time of the estimate occurs after the last available measurement.

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Example: random constant

Estimate the value of a random constant. How many points do you need?



- The best estimate is the mean.
- Variance of the estimate decreases as $1/N$.

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Remarks and Questions

- For a stationary process that represents a random constant, averaging over more points results in an improved estimate.
- What will happen if the same is applied to a non-constant?
- If we have a measurement corrupted with noise, can we use the statistical properties of the noise, and compute an estimate that maximizes the probability that this measurement actually occurred?
- For real-time applications, can we solve the estimation problem recursively?

.4

1 Problem

Given State-Space Equations

$$\vec{x}_k = \mathbf{f}_k(\vec{x}_{k-1}, \vec{w}_{k-1}) \quad (1)$$

$$\vec{z}_k = \mathbf{h}_k(\vec{x}_k, \vec{v}_k) \quad (2)$$

where \vec{x}_k is $(n \times 1)$ state vector at time k , \mathbf{f}_k and \mathbf{h}_k are possibly non-linear function $\mathbf{f}_k : \mathfrak{R}^n \times \mathfrak{R}^{n_w} \mapsto \mathfrak{R}^n$ and $\mathbf{h}_k : \mathfrak{R}^n \times \mathfrak{R}^{n_v} \mapsto \mathfrak{R}^m$, respectively, and \vec{w}_k and \vec{v}_k i.i.d state noise. The state process is Markov chain, i.e., $p(\vec{x}_k | \vec{x}_1, \dots, \vec{x}_{k-1}) = p(\vec{x}_k | \vec{x}_{k-1})$ and the distribution of \vec{z}_k conditional on the state \vec{x}_k is independent of previous state and measurement values, i.e., $p(\vec{z}_k | \vec{x}_{1:k}, \vec{z}_{1:k-1}) = p(\vec{z}_k | \vec{x}_k)$

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Objective

Probabilistically estimate \vec{x}_k using previous measurement $\vec{z}_{1:k}$. In other words, construct the pdf $p(\vec{x}_k | \vec{z}_{1:k})$.

Optimal MMSE Estimate

$$\mathbb{E}\{\|\vec{x}_k - \hat{\vec{x}}_k\|^2 | \vec{z}_{1:k}\} = \int \|\vec{x}_k - \hat{\vec{x}}_k\|^2 p(\vec{x}_k | \vec{z}_{1:k}) d\vec{x}_k \quad (3)$$

in other words find the conditional mean

$$\hat{\vec{x}}_k = \mathbb{E}\{\vec{x}_k | \vec{z}_{1:k}\} = \int \vec{x}_k p(\vec{x}_k | \vec{z}_{1:k}) d\vec{x}_k \quad (4)$$

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2 Bayesian Estimation

3 Kalman Filter

Assumptions

- \vec{w}_k and \vec{v}_k are drawn from a Gaussian distribution, uncorrelated have zero mean and statistically independent.

$$\mathbb{E}\{\vec{w}_k \vec{w}_i^T\} = \begin{cases} \mathbf{Q}_k & i = k \\ 0 & i \neq k \end{cases} \quad (5)$$

$$\mathbb{E}\{\vec{v}_k \vec{v}_i^T\} = \begin{cases} \mathbf{R}_k & i = k \\ 0 & i \neq k \end{cases} \quad (6)$$

$$\mathbb{E}\{\vec{w}_k \vec{v}_i^T\} = \begin{cases} 0 & \forall i, k \end{cases} \quad (7)$$

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Assumptions

- \mathbf{f}_k and \mathbf{h}_k are both linear, e.g., the state-space system equations may be written as

$$\vec{\mathbf{x}}_k = \Phi_{k-1} \vec{\mathbf{x}}_{k-1} + \vec{\mathbf{w}}_{k-1} \quad (8)$$

$$\vec{\mathbf{y}}_k = \mathbf{H}_k \vec{\mathbf{x}}_k + \vec{\mathbf{v}}_k \quad (9)$$

where Φ_{k-1} is $(n \times n)$ transition matrix relating $\vec{\mathbf{x}}_{k-1}$ to $\vec{\mathbf{x}}_k$, \mathbf{H}_k is $(m \times n)$ matrix provides noiseless connection between measurement and state vectors.

.8

State-Space Equations

$$\hat{\vec{\mathbf{x}}}_{k|k-1} = \Phi_{k-1} \hat{\vec{\mathbf{x}}}_{k-1|k-1} \quad (10)$$

$$\mathbf{P}_{k|k-1} = \mathbf{Q}_{k-1} + \Phi_{k-1} \mathbf{P}_{k-1|k-1} \Phi_{k-1}^T \quad (11)$$

$$\hat{\vec{\mathbf{x}}}_{k|k} = \hat{\vec{\mathbf{x}}}_{k|k-1} + \mathbf{K}_k (\vec{\mathbf{z}}_k - \mathbf{H}_k \hat{\vec{\mathbf{x}}}_{k|k-1}) \quad (12)$$

$$\mathbf{P}_{k|k} = (\mathbf{I} - \mathbf{K}_k \mathbf{H}_k) \mathbf{P}_{k|k-1} \quad (13)$$

where \mathbf{K}_k is $(n \times m)$ Kalman gain, and $(\vec{\mathbf{z}}_k - \mathbf{H}_k \hat{\vec{\mathbf{x}}}_{k|k-1})$ is the measurement innovation.

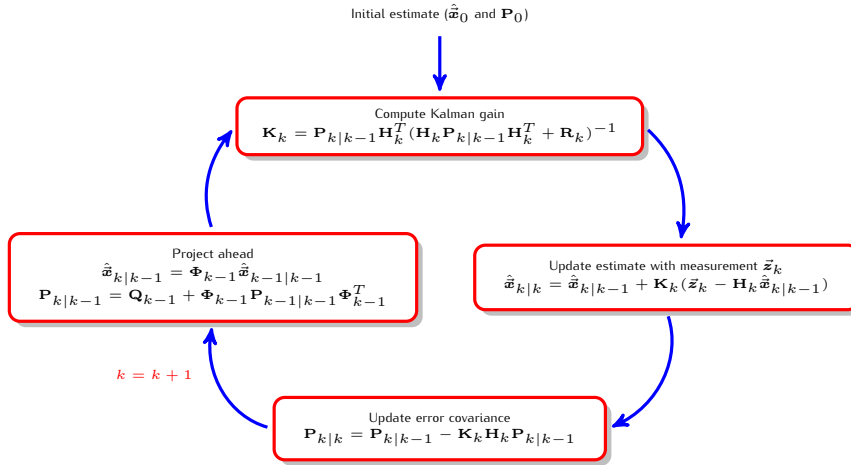
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Kalman Gain

$$\mathbf{K}_k = \mathbf{P}_{k|k-1} \mathbf{H}_k^T (\mathbf{H}_k \mathbf{P}_{k|k-1} \mathbf{H}_k^T + \mathbf{R}_k)^{-1} \quad (14)$$

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Kalman filter data flow



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System Model

$$\dot{\vec{\mathbf{x}}}(t) = \mathbf{F}(t) \vec{\mathbf{x}}(t) + \mathbf{G}(t) \vec{\mathbf{w}}(t) \quad (15)$$

To obtain the state vector estimate $\hat{\vec{\mathbf{x}}}(t)$

$$\mathbb{E}\{\dot{\vec{\mathbf{x}}}(t)\} = \frac{\partial}{\partial t} \hat{\vec{\mathbf{x}}}(t) = \mathbf{F}(t) \hat{\vec{\mathbf{x}}}(t) \quad (16)$$

Solving the above equation over the interval $t - \tau_s, t$

$$\hat{\vec{\mathbf{x}}}(t) = e^{(\int_{t-\tau_s}^t \mathbf{F}(t') dt')} \hat{\vec{\mathbf{x}}}(t - \tau_s) \quad (17)$$

where \mathbf{F}_{k-1} is the average of \mathbf{F} at times t and $t - \tau_s$.

.12

System Model Discretization

As shown in the Kalman filter equations the state vector estimate is given by

$$\hat{\mathbf{x}}_{k|k-1} = \Phi_{k-1} \hat{\mathbf{x}}_{k-1|k-1}$$

Therefore,

$$\Phi_{k-1} = e^{\mathbf{F}_{k-1} \tau_s} \approx \mathbf{I} + \mathbf{F}_{k-1} \tau_s \quad (18)$$

where \mathbf{F}_{k-1} is the average of \mathbf{F} at times t and $t - \tau_s$, and first order approximation is used.

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Discrete Covariance Matrix \mathbf{Q}_k

Assuming white noise, small time step, \mathbf{G} is constant over the integration period, and the trapezoidal integration

$$\mathbf{Q}_{k-1} \approx \frac{1}{2} [\Phi_{k-1} \mathbf{G}_{k-1} \mathbf{Q}(t_{k-1}) \mathbf{G}_{k-1}^T \Phi_{k-1}^T + \mathbf{G}_{k-1} \mathbf{Q}(t_{k-1}) \mathbf{G}_{k-1}^T] \tau_s \quad (19)$$

where

$$\mathbb{E}\{\vec{\mathbf{w}}(\eta) \vec{\mathbf{w}}^T(\zeta)\} = \mathbf{Q}(\eta) \delta(\eta - \zeta) \quad (20)$$

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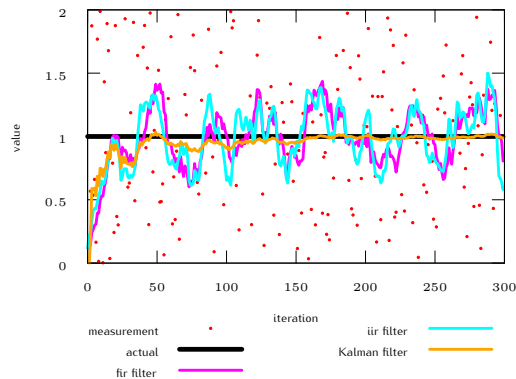
4 Example

Example: random constant

$$\dot{x}(t) = 0, \quad y_k = x_k + v_k$$

Design a Kalman filter to estimate x_k

- What is the discretized system?
- What is ϕ , Q , H , R and P ?



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Example: first order Markov noise

State Equation

$$\dot{b}(t) = -\frac{1}{T_c}b(t) + w(t) \quad (21)$$

Autocorrelation Function

$$\mathbb{E}\{b(t)b(t+\tau)\} = \sigma_{BI}^2 e^{-|\tau|/T_c} \quad (22)$$

where

$$\mathbb{E}\{w(t)w(t+\tau)\} = Q(t)\delta(t-\tau) \quad (23)$$

$$Q(t) = \frac{2\sigma_{BI}^2}{T_c} \quad (24)$$

and T_c is the correlation time.

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Discrete First Order Markov Noise

State Equation

$$b_k = e^{-\frac{1}{T_c}\tau_s} b_{k-1} + w_{k-1} \quad (25)$$

System Covariance Matrix

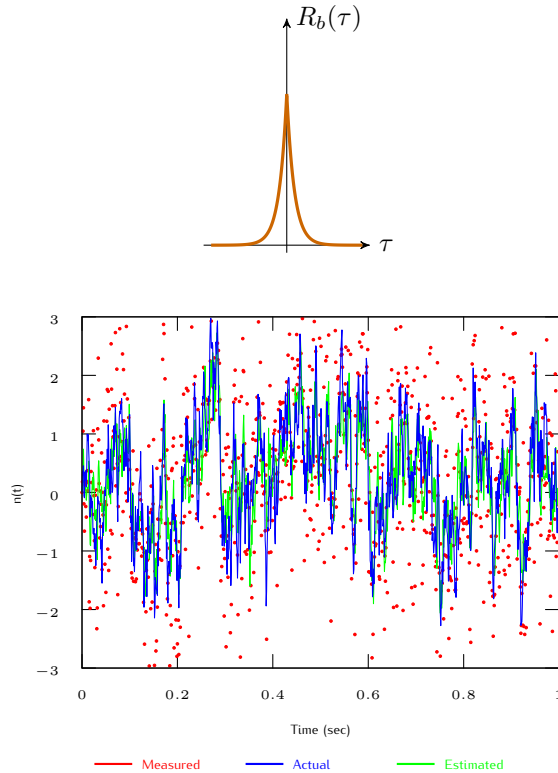
$$Q = \sigma_{BI}^2 [1 - e^{-\frac{2}{T_c}\tau_s}] \quad (26)$$

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Autocorrelation of 1st order Markov

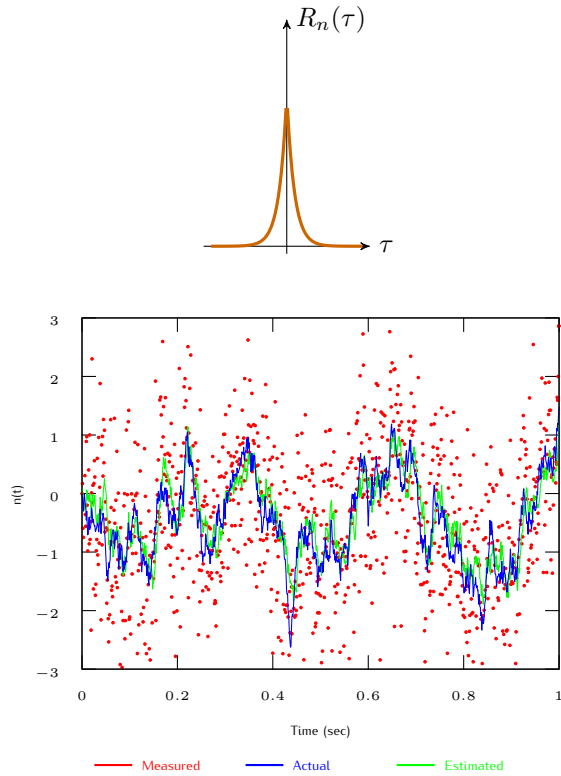
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Small Correlation Time $T_c = 0.01$



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Larger Correlation Time $T_c = 0.1$



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5 EKF

Linearized System

$$\mathbf{F}_k = \left. \frac{\partial \mathbf{f}(\vec{x})}{\partial \vec{x}} \right|_{\vec{x}=\hat{\vec{x}}_{k|k-1}}, \quad \mathbf{H}_k = \left. \frac{\partial \mathbf{h}(\vec{x})}{\partial \vec{x}} \right|_{\vec{x}=\hat{\vec{x}}_{k|k-1}} \quad (27)$$

where

$$\frac{\partial \mathbf{f}(\vec{x})}{\partial \vec{x}} = \begin{pmatrix} \frac{\partial f_1}{\partial x_1} & \frac{\partial f_1}{\partial x_2} & \dots \\ \frac{\partial f_2}{\partial x_1} & \frac{\partial f_2}{\partial x_2} & \dots \\ \vdots & \ddots & \vdots \end{pmatrix}, \quad \frac{\partial \mathbf{h}(\vec{x})}{\partial \vec{x}} = \begin{pmatrix} \frac{\partial h_1}{\partial x_1} & \frac{\partial h_1}{\partial x_2} & \dots \\ \frac{\partial h_2}{\partial x_1} & \frac{\partial h_2}{\partial x_2} & \dots \\ \vdots & \ddots & \vdots \end{pmatrix} \quad (28)$$

.21

Sequential Processing

If R is a block matrix, i.e., $R = \text{diag}(R^1, R^2, \dots, R^r)$. The R^i has dimensions $p^i \times p^i$. Then, we can sequentially process the measurements as:

For $i = 1, 2, \dots, r$

$$\mathbf{K}^i = \mathbf{P}^{i-1} (\mathbf{H}^i)^T (\mathbf{H}^i \mathbf{P}^{i-1} (\mathbf{H}^i)^T + \mathbf{R}^i)^{-1} \quad (29)$$

$$\hat{\vec{x}}_{k|k}^i = \hat{\vec{x}}_{k|k}^{i-1} + \mathbf{K}^i (\mathbf{z}_k^i - \mathbf{H}^i \hat{\vec{x}}_{k|k}^{i-1}) \quad (30)$$

$$\mathbf{P}^i = (\mathbf{I} - \mathbf{K}^i \mathbf{H}^i) \mathbf{P}^{i-1} \quad (31)$$

where $\hat{\vec{x}}_{k|k}^0 = \hat{\vec{x}}_{k|k-1}$, $\mathbf{P}^0 = \mathbf{P}_{k|k-1}^0$ and \mathbf{H}^i is $p^i \times n$ corresponding to the rows of \mathbf{H} corresponding the measurement being processed.

.22

Observability

The system is observable if the observability matrix

$$\mathcal{O}(k) = \begin{bmatrix} \mathbf{H}(k-n+1) \\ \mathbf{H}(k-n-2)\Phi(k-n+1) \\ \vdots \\ \mathbf{H}(k)\Phi(k-1)\dots\Phi(k-n+1) \end{bmatrix} \quad (32)$$

where n is the number of states, has a rank of n . The rank of \mathcal{O} is a binary indicator and does **not** provide a measure of how close the system is to being unobservable, hence, is prone to numerical ill-conditioning. .23

A Better Observability Measure

In addition to the computation of the rank of $\mathcal{O}(k)$, compute the Singular Value Decomposition (SVD) of $\mathcal{O}(k)$ as

$$\mathcal{O} = U\Sigma V^* \quad (33)$$

and observe the diagonal values of the matrix Σ . Using this approach it is possible to monitor the variations in the system observability due to changes in system dynamics. .24

Remarks

- Kalman filter is optimal under the aforementioned assumptions,
- and it is also an unbiased and minimum variance estimate.
- If the Gaussian assumptions is not true, Kalman filter is biased and not minimum variance.
- Observability is dynamics dependent.
- The error covariance update may be implemented using the *Joseph form* which provides a more stable solution due to the guaranteed symmetry.

$$\mathbf{P}_{k|k} = (\mathbf{I} - \mathbf{K}_k\mathbf{H}_k) \mathbf{P}_{k|k-1} (\mathbf{I} - \mathbf{K}_k\mathbf{H}_k)^T + \mathbf{K}_k\mathbf{R}_k\mathbf{K}_k^T \quad (34)$$

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6 Other Solutions

Unscented Kalman Filter (UKF)

Propagates carefully chosen sample points (using unscented transformation) through the true non-linear system, and therefore captures the posterior mean and covariance accurately to the second order. .26

Particle Filter

A Monte Carlo based method. It allows for a complete representation of the state distribution function. Unlike EKF and UKF, particle filters do not require the Gaussian assumptions. .27

7 References

[Bayesian Filtering: From Kalman Filters to Particle Filters, and Beyond](#), by Zhe Chen .28