

Lecture 3: Bayesian Filtering Equations and Kalman Filter

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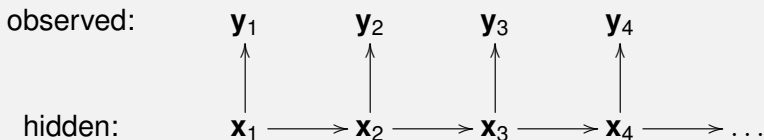
Probabilistic State Space Models: General Model

- General **probabilistic state space model**:

$$\text{dynamic model: } \mathbf{x}_k \sim p(\mathbf{x}_k | \mathbf{x}_{k-1})$$

$$\text{measurement model: } \mathbf{y}_k \sim p(\mathbf{y}_k | \mathbf{x}_k)$$

- $\mathbf{x}_k = (x_{k1}, \dots, x_{kn})$ is the **state** and $\mathbf{y}_k = (y_{k1}, \dots, y_{km})$ is the **measurement**.
- Has the form of **hidden Markov model** (HMM):



Example (Gaussian random walk)

Gaussian random walk model can be written as

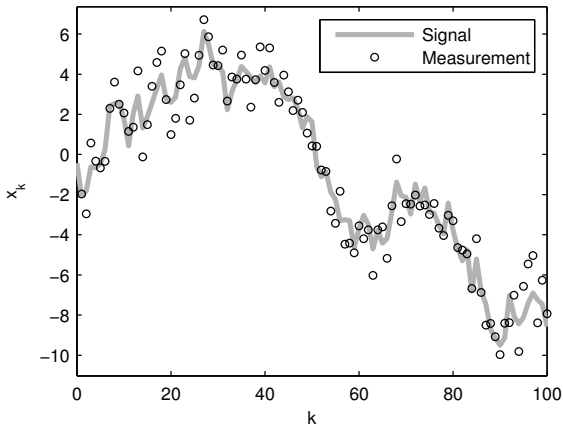
$$\begin{aligned}x_k &= x_{k-1} + w_{k-1}, & w_{k-1} &\sim \mathcal{N}(0, q) \\ y_k &= x_k + e_k, & e_k &\sim \mathcal{N}(0, r),\end{aligned}$$

where x_k is the hidden state and y_k is the measurement. In terms of probability densities the model can be written as

$$\begin{aligned}p(x_k | x_{k-1}) &= \frac{1}{\sqrt{2\pi q}} \exp\left(-\frac{1}{2q}(x_k - x_{k-1})^2\right) \\ p(y_k | x_k) &= \frac{1}{\sqrt{2\pi r}} \exp\left(-\frac{1}{2r}(y_k - x_k)^2\right)\end{aligned}$$

which is a discrete-time state space model.

Example (Gaussian random walk (cont.))



- Linear **Gauss-Markov model**:

$$\mathbf{x}_k = \mathbf{A}_{k-1} \mathbf{x}_{k-1} + \mathbf{q}_{k-1}$$

$$\mathbf{y}_k = \mathbf{H}_k \mathbf{x}_k + \mathbf{r}_k,$$

- Gaussian driven **non-linear model**:

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

$$\mathbf{y}_k = \mathbf{h}(\mathbf{x}_k, \mathbf{r}_k).$$

- Hierarchical and/or non-Gaussian models**

$$\mathbf{q}_{k-1} \sim \text{Dirichlet}(\mathbf{q}_{k-1} \mid \boldsymbol{\alpha})$$

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

$$\sigma_k^2 \sim \text{InvGamma}(\sigma_k^2 \mid \sigma_{k-1}^2, \gamma)$$

$$\mathbf{r}_k \sim \text{N}(\mathbf{0}, \sigma_k^2 \mathbf{I})$$

$$\mathbf{y}_k = \mathbf{h}(\mathbf{x}_k, \mathbf{r}_k).$$

Probabilistic State Space Models: Markov and Independence Assumptions

- The dynamic model $p(\mathbf{x}_k | \mathbf{x}_{k-1})$ is **Markovian**:
 - 1 **Future** \mathbf{x}_k is **independent** of the **past** given the present (here “present” is \mathbf{x}_{k-1}):

$$p(\mathbf{x}_k | \mathbf{x}_{1:k-1}, \mathbf{y}_{1:k-1}) = p(\mathbf{x}_k | \mathbf{x}_{k-1}).$$

- 2 **Past** \mathbf{x}_{k-1} is **independent** of the **future** given the present (here “present” is \mathbf{x}_k):

$$p(\mathbf{x}_{k-1} | \mathbf{x}_{k:T}, \mathbf{y}_{k:T}) = p(\mathbf{x}_{k-1} | \mathbf{x}_k).$$

- The **measurements** \mathbf{y}_k are **conditionally independent** given \mathbf{x}_k :

$$p(\mathbf{y}_k | \mathbf{x}_{1:k}, \mathbf{y}_{1:k-1}) = p(\mathbf{y}_k | \mathbf{x}_k).$$

Bayesian Filter: Principle

- **Bayesian filter** computes the **distribution**

$$p(\mathbf{x}_k | \mathbf{y}_{1:k})$$

- Given the following:
 - 1 Prior distribution $p(\mathbf{x}_0)$.
 - 2 State space model:

$$\mathbf{x}_k \sim p(\mathbf{x}_k | \mathbf{x}_{k-1})$$

$$\mathbf{y}_k \sim p(\mathbf{y}_k | \mathbf{x}_k),$$

- 3 Measurement sequence $\mathbf{y}_{1:k} = \mathbf{y}_1, \dots, \mathbf{y}_k$.
- Computation is based on **recursion rule** for incorporation of the new measurement \mathbf{y}_k into the posterior:

$$p(\mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}) \longrightarrow p(\mathbf{x}_k | \mathbf{y}_{1:k})$$

Bayesian Filter: Derivation of Prediction Step

- Assume that we know the posterior distribution of **previous time step**:

$$p(\mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}).$$

- The joint distribution of $\mathbf{x}_k, \mathbf{x}_{k-1}$ given $\mathbf{y}_{1:k-1}$ can be computed as (recall the Markov property):

$$\begin{aligned} p(\mathbf{x}_k, \mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}) &= p(\mathbf{x}_k | \mathbf{x}_{k-1}, \mathbf{y}_{1:k-1}) p(\mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}) \\ &= p(\mathbf{x}_k | \mathbf{x}_{k-1}) p(\mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}), \end{aligned}$$

- Integrating over \mathbf{x}_{k-1} gives the **Chapman-Kolmogorov equation**

$$p(\mathbf{x}_k | \mathbf{y}_{1:k-1}) = \int p(\mathbf{x}_k | \mathbf{x}_{k-1}) p(\mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}) d\mathbf{x}_{k-1}.$$

- This is the **prediction step** of the Bayesian filter.

Bayesian Filter: Derivation of Update Step

- Now we have:

- 1 **Prior distribution** from the Chapman-Kolmogorov equation

$$p(\mathbf{x}_k | \mathbf{y}_{1:k-1})$$

- 2 **Measurement likelihood** from the state space model:

$$p(\mathbf{y}_k | \mathbf{x}_k)$$

- The posterior distribution can be computed by the **Bayes' rule** (recall the conditional independence of measurements):

$$\begin{aligned} p(\mathbf{x}_k | \mathbf{y}_{1:k}) &= \frac{1}{Z_k} p(\mathbf{y}_k | \mathbf{x}_k, \mathbf{y}_{1:k-1}) p(\mathbf{x}_k | \mathbf{y}_{1:k-1}) \\ &= \frac{1}{Z_k} p(\mathbf{y}_k | \mathbf{x}_k) p(\mathbf{x}_k | \mathbf{y}_{1:k-1}) \end{aligned}$$

- This is the **update step** of the Bayesian filter.

Bayesian Filter: Formal Equations

Bayesian filter

- **Initialization:** The recursion starts from the prior distribution $p(\mathbf{x}_0)$.
- **Prediction:** by the Chapman-Kolmogorov equation

$$p(\mathbf{x}_k | \mathbf{y}_{1:k-1}) = \int p(\mathbf{x}_k | \mathbf{x}_{k-1}) p(\mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}) d\mathbf{x}_{k-1}.$$

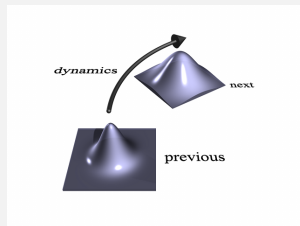
- **Update:** by the Bayes' rule

$$p(\mathbf{x}_k | \mathbf{y}_{1:k}) = \frac{1}{Z_k} p(\mathbf{y}_k | \mathbf{x}_k) p(\mathbf{x}_k | \mathbf{y}_{1:k-1}).$$

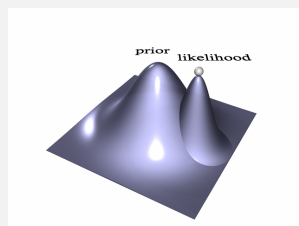
- **The normalization constant** $Z_k = p(\mathbf{y}_k | \mathbf{y}_{1:k-1})$ is given as

$$Z_k = \int p(\mathbf{y}_k | \mathbf{x}_k) p(\mathbf{x}_k | \mathbf{y}_{1:k-1}) d\mathbf{x}_k.$$

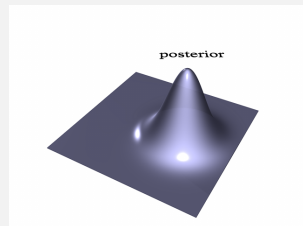
Bayesian Filter: Graphical Explanation



On prediction step the distribution of previous step is propagated through the dynamics.



Prior distribution from prediction and the likelihood of measurement.



The posterior distribution after combining the prior and likelihood by Bayes' rule.

- Gaussian driven **linear model**, i.e., **Gauss-Markov model**:

$$\mathbf{x}_k = \mathbf{A}_{k-1} \mathbf{x}_{k-1} + \mathbf{q}_{k-1}$$

$$\mathbf{y}_k = \mathbf{H}_k \mathbf{x}_k + \mathbf{r}_k,$$

- $\mathbf{q}_{k-1} \sim \mathcal{N}(\mathbf{0}, \mathbf{Q}_{k-1})$ white **process noise**.
- $\mathbf{r}_k \sim \mathcal{N}(\mathbf{0}, \mathbf{R}_k)$ white **measurement noise**.
- \mathbf{A}_{k-1} is the **transition matrix** of the **dynamic model**.
- \mathbf{H}_k is the **measurement model** matrix.
- In **probabilistic terms** the model is

$$p(\mathbf{x}_k | \mathbf{x}_{k-1}) = \mathcal{N}(\mathbf{x}_k | \mathbf{A}_{k-1} \mathbf{x}_{k-1}, \mathbf{Q}_{k-1})$$

$$p(\mathbf{y}_k | \mathbf{x}_k) = \mathcal{N}(\mathbf{y}_k | \mathbf{H}_k \mathbf{x}_k, \mathbf{R}_k).$$

- Gaussian probability density

$$N(\mathbf{x} \mid \mathbf{m}, \mathbf{P}) = \frac{1}{(2\pi)^{n/2} |\mathbf{P}|^{1/2}} \exp\left(-\frac{1}{2}(\mathbf{x} - \mathbf{m})^T \mathbf{P}^{-1} (\mathbf{x} - \mathbf{m})\right),$$

- Let \mathbf{x} and \mathbf{y} have the Gaussian densities

$$p(\mathbf{x}) = N(\mathbf{x} \mid \mathbf{m}, \mathbf{P}), \quad p(\mathbf{y} \mid \mathbf{x}) = N(\mathbf{y} \mid \mathbf{H}\mathbf{x}, \mathbf{R}),$$

- Then the joint and marginal distributions are

$$\begin{pmatrix} \mathbf{x} \\ \mathbf{y} \end{pmatrix} \sim N\left(\begin{pmatrix} \mathbf{m} \\ \mathbf{H}\mathbf{m} \end{pmatrix}, \begin{pmatrix} \mathbf{P} & \mathbf{P}\mathbf{H}^T \\ \mathbf{H}\mathbf{P} & \mathbf{H}\mathbf{P}\mathbf{H}^T + \mathbf{R} \end{pmatrix}\right)$$
$$\mathbf{y} \sim N(\mathbf{H}\mathbf{m}, \mathbf{H}\mathbf{P}\mathbf{H}^T + \mathbf{R}).$$

Kalman Filter: Derivation Preliminaries (cont.)

- If the random variables \mathbf{x} and \mathbf{y} have the joint Gaussian probability density

$$\begin{pmatrix} \mathbf{x} \\ \mathbf{y} \end{pmatrix} \sim N \left(\begin{pmatrix} \mathbf{a} \\ \mathbf{b} \end{pmatrix}, \begin{pmatrix} \mathbf{A} & \mathbf{C} \\ \mathbf{C}^T & \mathbf{B} \end{pmatrix} \right),$$

- Then the marginal and conditional densities of \mathbf{x} and \mathbf{y} are given as follows:

$$\mathbf{x} \sim N(\mathbf{a}, \mathbf{A})$$

$$\mathbf{y} \sim N(\mathbf{b}, \mathbf{B})$$

$$\mathbf{x} | \mathbf{y} \sim N(\mathbf{a} + \mathbf{C}\mathbf{B}^{-1}(\mathbf{y} - \mathbf{b}), \mathbf{A} - \mathbf{C}\mathbf{B}^{-1}\mathbf{C}^T)$$

$$\mathbf{y} | \mathbf{x} \sim N(\mathbf{b} + \mathbf{C}^T\mathbf{A}^{-1}(\mathbf{x} - \mathbf{a}), \mathbf{B} - \mathbf{C}^T\mathbf{A}^{-1}\mathbf{C}).$$

Kalman Filter: Derivation of Prediction Step

- Assume that the posterior distribution of previous step is Gaussian

$$p(\mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}) = \mathbf{N}(\mathbf{x}_{k-1} | \mathbf{m}_{k-1}, \mathbf{P}_{k-1}).$$

- The **Chapman-Kolmogorov** equation now gives

$$\begin{aligned} p(\mathbf{x}_k | \mathbf{y}_{1:k-1}) &= \int p(\mathbf{x}_k | \mathbf{x}_{k-1}) p(\mathbf{x}_{k-1} | \mathbf{y}_{1:k-1}) d\mathbf{x}_{k-1} \\ &= \int \mathbf{N}(\mathbf{x}_k | \mathbf{A}_{k-1} \mathbf{x}_{k-1}, \mathbf{Q}_{k-1}) \mathbf{N}(\mathbf{x}_{k-1} | \mathbf{m}_{k-1}, \mathbf{P}_{k-1}). \end{aligned}$$

- Using the Gaussian distribution computation rules from previous slides, we get the **prediction step**

$$\begin{aligned} p(\mathbf{x}_k | \mathbf{y}_{1:k-1}) &= \mathbf{N}(\mathbf{x}_k | \mathbf{A}_{k-1} \mathbf{m}_{k-1}, \mathbf{A}_{k-1} \mathbf{P}_{k-1} \mathbf{A}_{k-1}^T + \mathbf{Q}_{k-1}) \\ &= \mathbf{N}(\mathbf{x}_k | \mathbf{m}_k^-, \mathbf{P}_k^-) \end{aligned}$$

- The joint distribution of \mathbf{y}_k and \mathbf{x}_k is

$$\begin{aligned} p(\mathbf{x}_k, \mathbf{y}_k \mid \mathbf{y}_{1:k-1}) &= p(\mathbf{y}_k \mid \mathbf{x}_k) p(\mathbf{x}_k \mid \mathbf{y}_{1:k-1}) \\ &= N \left(\begin{bmatrix} \mathbf{x}_k \\ \mathbf{y}_k \end{bmatrix} \mid \mathbf{m}'', \mathbf{P}'' \right), \end{aligned}$$

where

$$\begin{aligned} \mathbf{m}'' &= \begin{pmatrix} \mathbf{m}_k^- \\ \mathbf{H}_k \mathbf{m}_k^- \end{pmatrix} \\ \mathbf{P}'' &= \begin{pmatrix} \mathbf{P}_k^- & \mathbf{P}_k^- \mathbf{H}_k^T \\ \mathbf{H}_k \mathbf{P}_k^- & \mathbf{H}_k \mathbf{P}_k^- \mathbf{H}_k^T + \mathbf{R}_k \end{pmatrix}. \end{aligned}$$

- The conditional distribution of \mathbf{x}_k given \mathbf{y}_k is then given as

$$\begin{aligned} p(\mathbf{x}_k | \mathbf{y}_k, \mathbf{y}_{1:k-1}) &= p(\mathbf{x}_k | \mathbf{y}_{1:k}) \\ &= \mathbf{N}(\mathbf{x}_k | \mathbf{m}_k, \mathbf{P}_k), \end{aligned}$$

where

$$\mathbf{S}_k = \mathbf{H}_k \mathbf{P}_k^- \mathbf{H}_k^T + \mathbf{R}_k$$

$$\mathbf{K}_k = \mathbf{P}_k^- \mathbf{H}_k^T \mathbf{S}_k^{-1}$$

$$\mathbf{m}_k = \mathbf{m}_k^- + \mathbf{K}_k [\mathbf{y}_k - \mathbf{H}_k \mathbf{m}_k^-]$$

$$\mathbf{P}_k = \mathbf{P}_k^- - \mathbf{K}_k \mathbf{S}_k \mathbf{K}_k^T.$$

Kalman Filter

- Initialization: $\mathbf{x}_0 \sim \mathcal{N}(\mathbf{m}_0, \mathbf{P}_0)$
- Prediction step:

$$\mathbf{m}_k^- = \mathbf{A}_{k-1} \mathbf{m}_{k-1}$$

$$\mathbf{P}_k^- = \mathbf{A}_{k-1} \mathbf{P}_{k-1} \mathbf{A}_{k-1}^T + \mathbf{Q}_{k-1}.$$

- Update step:

$$\mathbf{v}_k = \mathbf{y}_k - \mathbf{H}_k \mathbf{m}_k^-$$

$$\mathbf{S}_k = \mathbf{H}_k \mathbf{P}_k^- \mathbf{H}_k^T + \mathbf{R}_k$$

$$\mathbf{K}_k = \mathbf{P}_k^- \mathbf{H}_k^T \mathbf{S}_k^{-1}$$

$$\mathbf{m}_k = \mathbf{m}_k^- + \mathbf{K}_k \mathbf{v}_k$$

$$\mathbf{P}_k = \mathbf{P}_k^- - \mathbf{K}_k \mathbf{S}_k \mathbf{K}_k^T.$$

Kalman Filter: Properties

- Kalman filter can be applied only to **linear Gaussian models**, for non-linearities we need e.g. EKF or UKF.
- If several **conditionally independent measurements** are obtained at a single time step, update step is simply performed for each of them separately.
- \Rightarrow If the measurement noise covariance is diagonal (as it usually is), **no matrix inversion** is needed at all.
- The **covariance equation is independent of measurements** – the gain sequence could be computed and stored offline.
- If the model is **time-invariant**, the gain converges to a constant $\mathbf{K}_k \rightarrow \mathbf{K}$ and the filter becomes stationary:

$$\mathbf{m}_k = (\mathbf{A} - \mathbf{KHA}) \mathbf{m}_{k-1} + \mathbf{K} \mathbf{y}_k$$

Example (Kalman filter for Gaussian random walk)

Filtering density is Gaussian

$$p(x_{k-1} | y_{1:k-1}) = N(x_{k-1} | m_{k-1}, P_{k-1}).$$

The Kalman filter prediction and update equations are

$$m_k^- = m_{k-1}$$

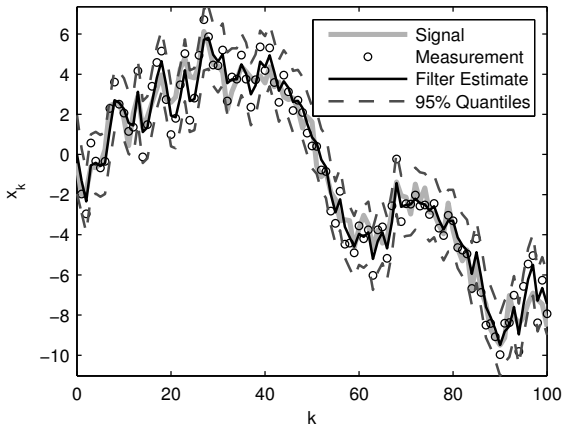
$$P_k^- = P_{k-1} + q$$

$$m_k = m_k^- + \frac{P_k^-}{P_k^- + r} (y_k - m_k^-)$$

$$P_k = P_k^- - \frac{(P_k^-)^2}{P_k^- + r}.$$

Kalman Filter: Random Walk Example (cont.)

Example (Kalman filter for Gaussian random walk (cont.))



Kalman Filter: Car Tracking Example [1/4]

The dynamic model of the car tracking model from the first lecture can be written in discrete form as follows:

$$\begin{pmatrix} x_k \\ y_k \\ \dot{x}_k \\ \dot{y}_k \end{pmatrix} = \underbrace{\begin{pmatrix} 1 & 0 & \Delta t & 0 \\ 0 & 1 & 0 & \Delta t \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}}_{\mathbf{A}} \begin{pmatrix} x_{k-1} \\ y_{k-1} \\ \dot{x}_{k-1} \\ \dot{y}_{k-1} \end{pmatrix} + \mathbf{q}_{k-1}$$

where \mathbf{q}_k is zero mean with a covariance matrix \mathbf{Q} .

$$\mathbf{Q} = \begin{pmatrix} q_1^c \Delta t^3 / 3 & 0 & q_1^c \Delta t^2 / 2 & 0 \\ 0 & q_2^c \Delta t^3 / 3 & 0 & q_2^c \Delta t^2 / 2 \\ q_1^c \Delta t^2 / 2 & 0 & q_1^c \Delta t & 0 \\ 0 & q_2^c \Delta t^2 / 2 & 0 & q_2^c \Delta t \end{pmatrix}$$

The measurement model can be written in form

$$\mathbf{y}_k = \underbrace{\begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \end{pmatrix}}_{\mathbf{H}} \begin{pmatrix} x_k \\ y_k \\ \dot{x}_k \\ \dot{y}_k \end{pmatrix} + \mathbf{e}_k,$$

where \mathbf{e}_k has the covariance

$$\mathbf{R} = \begin{pmatrix} \sigma^2 & 0 \\ 0 & \sigma^2 \end{pmatrix}$$

Kalman Filter: Car Tracking Example [3/4]

The Kalman filter prediction equations:

$$\mathbf{m}_k^- = \begin{pmatrix} 1 & 0 & \Delta t & 0 \\ 0 & 1 & 0 & \Delta t \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix} \mathbf{m}_{k-1}$$
$$\mathbf{P}_k^- = \begin{pmatrix} 1 & 0 & \Delta t & 0 \\ 0 & 1 & 0 & \Delta t \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix} \mathbf{P}_{k-1} \begin{pmatrix} 1 & 0 & \Delta t & 0 \\ 0 & 1 & 0 & \Delta t \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{pmatrix}^T$$
$$+ \begin{pmatrix} q_1^c \Delta t^3 / 3 & 0 & q_1^c \Delta t^2 / 2 & 0 \\ 0 & q_2^c \Delta t^3 / 3 & 0 & q_2^c \Delta t^2 / 2 \\ q_1^c \Delta t^2 / 2 & 0 & q_1^c \Delta t & 0 \\ 0 & q_2^c \Delta t^2 / 2 & 0 & q_2^c \Delta t \end{pmatrix}$$

The Kalman filter update equations:

$$\mathbf{S}_k = \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \end{pmatrix} \mathbf{P}_k^- \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \end{pmatrix}^T + \begin{pmatrix} \sigma^2 & 0 \\ 0 & \sigma^2 \end{pmatrix}$$

$$\mathbf{K}_k = \mathbf{P}_k^- \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \end{pmatrix}^T \mathbf{S}_k^{-1}$$

$$\mathbf{m}_k = \mathbf{m}_k^- + \mathbf{K}_k \left(\mathbf{y}_k - \begin{pmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \end{pmatrix} \mathbf{m}_k^- \right)$$

$$\mathbf{P}_k = \mathbf{P}_k^- - \mathbf{K}_k \mathbf{S}_k \mathbf{K}_k^T$$

- **Probabilistic state space models** consist of Markovian **dynamic models** and conditionally independent **measurement models**.
- Special cases are, for example, **linear Gaussian models** and **non-linear and non-Gaussian models**.
- **Bayesian filtering equations** form the formal solution to general Bayesian filtering problem.
- The Bayesian filtering equations consist of **prediction** and **update** steps.
- **Kalman filter** is the closed form filtering solution to **linear Gaussian models**.

Matlab Demo: Kalman Filter Implementation

[Kalman filter for car tracking model]