

Homework 13

Spring 2023

1. Balls in Bins Estimation

You throw n balls into m bins, where $n \geq 1$ and $m \geq 2$. Each ball lands in each bin with the same probability, independently of all other events. Let X and Y be the number of balls in bin 1 and 2 respectively.

- a. What is $\mathbb{E}(Y \mid X)$?
- b. Define $\mathbb{Q}(Y \mid X)$ to be the best quadratic function in X that minimizes mean squared error when used to estimate Y . Without doing any mathematical work, what are $\mathbb{L}(Y \mid X)$ and $\mathbb{Q}(Y \mid X)$? Justify your answer.
- c. Your friend from UCLA who hasn't learned about the Hilbert space of random variables isn't convinced by your explanation. Use the formula

$$\mathbb{L}(Y \mid X) = \mathbb{E}(Y) + \frac{\text{cov}(X, Y)}{\text{var}(X)}(X - \mathbb{E}(X))$$

to calculate the LLSE and verify your claim.

2. Basic Properties of Jointly Gaussian Random Variables

Let (X_1, \dots, X_n) be a collection of jointly Gaussian random variables with mean vector μ and covariance matrix Σ . Their joint density is given by, for $x \in \mathbb{R}^n$,

$$f(x) = \frac{1}{\sqrt{(2\pi)^n \det \Sigma}} \exp \left\{ -\frac{1}{2} (x - \mu)^T \Sigma^{-1} (x - \mu) \right\}.$$

- a. Show that X_1, \dots, X_n are independent if and only if they are pairwise uncorrelated.
- b. Show that any linear combination of X_1, \dots, X_n will also be a Gaussian random variable.
Hint: Consider using moment-generating functions.

3. Gaussian Random Vector MMSE

Consider the Gaussian random vector

$$\begin{bmatrix} X \\ Y \end{bmatrix} \sim \mathcal{N}\left(\begin{bmatrix} 1 \\ 0 \end{bmatrix}, \begin{bmatrix} 2 & 1 \\ 1 & 2 \end{bmatrix}\right),$$

and define the sign of Y to be the random variable

$$W = \begin{cases} 1 & \text{if } Y > 0 \\ 0 & \text{if } Y = 0 \\ -1 & \text{if } Y < 0 \end{cases}.$$

- a. Find $\mathbb{E}(WX \mid Y)$.
- b. Is the LLSE $\mathbb{L}(WX \mid Y)$ the same as the MMSE you found in part a?
- c. Are WX and Y jointly Gaussian?

4. MMSE for Jointly Gaussian

Find $\mathbb{E}(X \mid Y, Z)$ for the jointly Gaussian random vector

$$\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} \sim \mathcal{N}\left(\mu = \begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}, \Sigma = \begin{bmatrix} 5 & 3 & 1 \\ 3 & 9 & 3 \\ 1 & 3 & 2 \end{bmatrix}\right).$$

5. Even-Times Kalman Filter

Consider a random process $(X_n)_{n \in \mathbb{N}}$ with state space model

$$\begin{aligned} X_{n+1} &= aX_n + V_n, & V_n &\sim_{\text{i.i.d.}} \mathcal{N}(0, \sigma_V^2) \\ Y_n &= X_n + W_n, & W_n &\sim_{\text{i.i.d.}} \mathcal{N}(0, \sigma_W^2) \end{aligned}$$

where $(V_n)_{n \in \mathbb{N}}$ and $(W_n)_{n \in \mathbb{N}}$ are independent. We can only observe the process at even times, i.e. we observe the random variables Y_0, Y_2, Y_4, \dots

- a. Derive a recurrence relation for the estimator $\hat{X}_{2n|2n} := \mathbb{E}(X_{2n} \mid Y_0, Y_2, \dots, Y_{2n})$ in terms of $\hat{X}_{2n-2|2n-2}$.
- b. Derive a recurrence relation for $\hat{X}_{2n+1|2n}$ in terms of $\hat{X}_{2n|2n}$.

6. Kalman Filter with Correlated Noise

Consider the state space model

$$\begin{aligned}X_n &= aX_{n-1} + V_n \\Y_n &= X_n + V_n,\end{aligned}$$

with $X_0 = 0$ and $(V_n)_{n \geq 0} \sim_{\text{i.i.d.}} \mathcal{N}(0, 1)$. Note that the observation noise is the same as the process noise V_n , not independent of it, so this is different from the usual Kalman filter model. Derive recursive update equations for $\hat{X}_{n|n} := \mathbb{L}(X_n \mid Y_0, \dots, Y_n)$.

Hint: You may use the fact that the equations will be of the form

$$\begin{aligned}\hat{X}_{n|n} &= a\hat{X}_{n-1|n-1} + K_n \tilde{Y}_n \\ \tilde{Y}_n &= Y_n - a\hat{X}_{n-1|n-1},\end{aligned}$$

where you should find the Kalman gain and the estimator covariance recurrence relation

$$\begin{aligned}K_n &= ? \\ \sigma_{n|n-1}^2 &= a^2 \sigma_{n-1|n-1}^2 + 1 \\ \sigma_{n|n}^2 &= ?(\sigma_{n|n-1}^2).\end{aligned}$$