
Hidden Markov Model I

- Assume there are two types of weather “Sunny” and “Rainy”. We assume, *a prior*, that the probabilities of two types of days are 0.7 and 0.3, e.g.,
 $Pr(Sunny) = 0.7, Pr(Rainy) = 0.3$.
- Every morning, you do two things: walk our dog (“W”) or reading (“R”). Assume the following conditional probabilities:

$$Pr(W|Sunny) = 0.8, Pr(R|Sunny) = 0.2.$$

$$Pr(W|Rainy) = 0.2, Pr(R|Rainy) = 0.8.$$

- Assume we know your morning activity for a number of days: {W, W, R, R, W, W, R, W, W, W}. How can we estimate the weather condition for each day?

- Using Bayes' rule, one can do for each day:

$$\begin{aligned} Pr(Sunny|W) &= \frac{Pr(W|Sunny)Pr(Sunny)}{Pr(W|Sunny)Pr(Sunny) + Pr(W|Rainy)Pr(Rainy)} \\ &= \frac{0.8 * 0.7}{0.8 * 0.7 + 0.2 * 0.3} = 0.9 \\ Pr(Sunny|R) &= \end{aligned}$$

- However, this assumes independence of observations and completely ignores the connections between weather changes, e.g., probability of today is Sunny given yesterday is Sunny, etc.
- With the consideration of those, today's weather $Pr(Sunny|W)$ should also depend on yesterday's weather, in addition to the W/R status.
- Such an approach can be formalized by a “hidden Markov model” (HMM).

- Assume we observe sequential data $\mathbf{u} = \{u_1, u_2, \dots, u_T\}$ (your morning activities).
- \mathbf{u} is generated by a **hidden**, unobserved state: $\mathbf{s} = \{s_1, s_2, \dots, s_T\}$.
- Each s_t can take M states, with “**initial probability**” $\pi_k, k = 1, \dots, M$:
 $Pr(s_1 = k) = \pi_k, \sum_k \pi_k = 1$.
- The distribution of \mathbf{u} conditional on \mathbf{s} is specified by a distribution $b_k(u)$:
 $u_t | s_t = k \sim b_k(u_t)$. This is called “**emission probability**”.
- The changes of states between consecutive hidden state is specified by
“**transition probability**”: $a_{k,l} = Pr(s_{t+1} = l | s_t = k)$. Or you can write this as $a_{k \rightarrow l}$.
- Assume the underlying states follow a **Markov chain**, that is, given present, the future is independent of the past:

$$Pr(s_{t+1} | s_t, s_{t-1}, \dots, s_1) = Pr(s_{t+1} | s_t).$$

To summarize: Observed data: \mathbf{u} . Missing data: \mathbf{s} . Parameters: $\lambda = \{\pi_k, b_k(u), a_{k,l}\}$.

Review: discrete time finite homogeneous Markov Chain— 4/22 —

- The possible states are included in a finite discrete set: $\{E_1, E_2, \dots, E_M\}$.
- From time t to $t + 1$, make stochastic movement from one state to another.
- Markov Property: the state of s_{t+1} only depends on the state of s_t , not the states before time t :

$$Pr(s_{t+1}|s_t, s_{t-1}, \dots, s_1) = Pr(s_{t+1}|s_t).$$

- Time-homogeneous transition probabilities property: $P(s_{t+1}|s_t)$ independent of t .
- Denote the transition probability matrix by \mathbf{A} . Define N step transition as:
 $a_{k,l}(N) = Pr(s_{t+N} = l | s_t = k)$. It can be shown that $\mathbf{A}(N) = \mathbf{A}^N$.

A HMM can answer following questions:

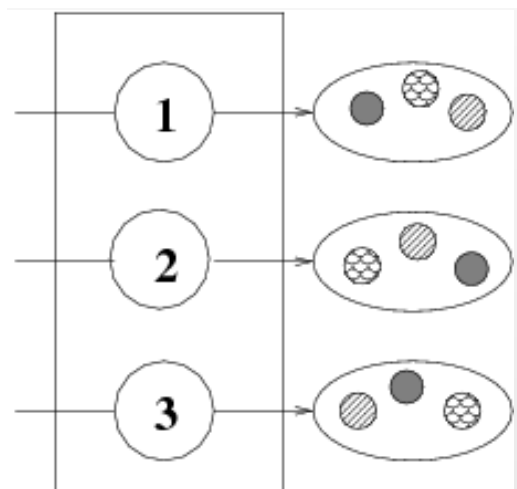
- Parameter estimation: estimate the initial/emission/transition probabilities.
 $\hat{\lambda} = \operatorname{argmax}_{\lambda} Pr(\mathbf{u}|\lambda)$.
- What are the probabilities of the underlying states, given the observations:
 $Pr(s|\mathbf{u})$.
- The most likely path: given the observed data, what are the most likely underlying states for all observations: $\hat{s} = \operatorname{argmax}_s Pr(s|\lambda, \mathbf{u})$.
- Predict future, e.g., $Pr(u_{t+1}|\mathbf{u}, \hat{\lambda})$.

Examples of HMM applications:

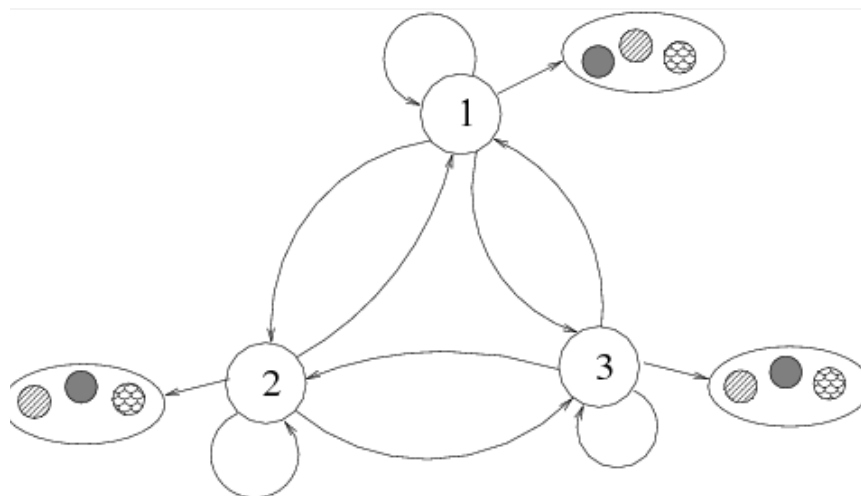
- Speech recognition.
- DNA sequence analysis, e.g., gene finding, sequence alignment.
- Financial time series data.

- There's close connection between a HMM and a mixture model: both have hidden states/group assignment, initial and emission probabilities.
- Difference is that mixture model assumes **independent** observations, HMM assumes sequential observation with transition probability.

Mixture model



HMM



According to Markov property, we have:

- Joint probability of hidden states:

$$\begin{aligned} P(s_1, s_2, \dots, s_T) &= P(s_1)P(s_2|s_1) \dots P(s_T|s_{T-1}) \\ &= \pi_{s_1} a_{s_1, s_2} \dots a_{s_{T-1}, s_T} \end{aligned}$$

- Conditional on the states, the observations are independent of each other:

$$P(u_i, u_j | \mathbf{s}) = P(u_i | \mathbf{s}) P(u_j | \mathbf{s})$$

So the joint probability of observations, given hidden states is:

$$P(\mathbf{u} | \mathbf{s}) = \prod_{i=1}^T P(u_i | s_i) = \prod_{i=1}^T b_{s_i}(u_i)$$

- Joint probability of hidden states and observed data

$$\begin{aligned}P(\mathbf{u}, \mathbf{s}) &= P(\mathbf{s})P(\mathbf{u}|\mathbf{s}) \\ &= \pi_{s_1} b_{s_1}(u_1) a_{s_1, s_2} b_{s_2}(u_2) a_{s_2, s_3} \cdots a_{s_{T-1}, s_T} b_{s_T}(u_T)\end{aligned}$$

- Marginal probability of observed data:

$$\begin{aligned}P(\mathbf{u}) &= \sum_{\mathbf{s}} P(\mathbf{s})P(\mathbf{u}|\mathbf{s}) \\ &= \sum_{\mathbf{s}} \pi_{s_1} b_{s_1}(u_1) a_{s_1, s_2} b_{s_2}(u_2) a_{s_2, s_3} \cdots a_{s_{T-1}, s_T} b_{s_T}(u_T)\end{aligned}$$

- First need to make parametric assumption of the emission probabilities $b_k(u)$.
- A common assumption is that $b_k(u)$ is Normal, e.g., $b_k(u) = N(u : \mu_k, \sigma_k^2)$.
- Then the model parameters to be estimated are:

$$\lambda = \{\pi_k, \mu_k, \sigma_k, a_{k,l} : k, l = 1, \dots, M\}$$

- One can obtain the MLEs for λ from the marginal probability of observed data. However it's very difficult because the marginal probability involves summing over all possible paths (\sum_s).
- Clever algorithm was invented to solve the problem.

- Define $L_k(t)$ be the conditional probability of being in state k at position t given the observed data \mathbf{u} :

$$L_k(t) = P(s_t = k | \mathbf{u})$$

- Define $H_{k,l}(t)$ be the conditional probability of being in state k at position t and being in state l at position $t + 1$ (i.e., seeing a transition from k to l at t), given the observed data \mathbf{u} :

$$H_{k,l}(t) = P(s_t = k, s_{t+1} = l | \mathbf{u})$$

- Note that $L_k(t) = \sum_{l=1}^M H_{k,l}(t)$, $\sum_{k=1}^M L_k(t) = 1$.

- Then the parameters can be estimated by EM:
 - E-step: Compute $L_k(t)$ and $H_{k,l}(t)$ given current parameters.
 - M-step: update parameters:

$$\begin{aligned}\mu_k &= \frac{\sum_{t=1}^T L_k(t) u_t}{\sum_{t=1}^T L_k(t)} \\ \sigma_k^2 &= \frac{\sum_{t=1}^T L_k(t) (u_t - \mu_k)^2}{\sum_{t=1}^T L_k(t)} \\ a_{k,l} &= \frac{\sum_{t=1}^{T-1} H_{k,l}(t)}{\sum_{t=1}^{T-1} L_k(t)} \\ \pi_k &= \frac{\sum_{t=1}^T L_k(t)}{T}\end{aligned}$$

- Derivation steps are similar to that in M-component normal mixture model (try it yourself). The new items are the transition probabilities.

- In the M-step to update Normal distribution parameters, $L_k(t)$ plays the same role as the posterior probability (expected value) of a component (state) given the observation, i.e., $p_{t,k} = P(s_t = k|u_t)$.
- In comparison, $L_k(t) = P(s_t = k|u_1, u_2, \dots, u_T)$.
- If one ignores the connections among observations, e.g., s_t 's are independent and thus u_t 's are iid, then $L_k(t) = p_{t,k}$, and HMM reduce to a M-component Normal mixture model.
- In a mixture model, s_t only depends on u_t because observations are independent.
- In a HMM, s_t depends on the entire sequence of observations because of the underlying Markov process.

The forward-backward algorithm is designed to efficiently compute:

$$L_k(t) = P(s_t = k | \mathbf{u})$$

$$H_{k,l}(t) = P(s_t = k, s_{t+1} = l | \mathbf{u})$$

- Define the **forward probability** $\alpha_k(t)$ as the **joint probability** of observing the first t data $u_i, i = 1, \dots, t$ and being in state k at time t :

$$\alpha_k(t) = P(u_1, u_2, \dots, u_t, s_t = k)$$

- The forward probability can be computed recursively:

$$\alpha_k(1) = \pi_k b_k(u_1) \quad 1 \leq k \leq M$$

$$\alpha_k(t) = b_k(u_t) \sum_{l=1}^M \alpha_l(t-1) a_{l,k} \quad 1 < t \leq T, 1 \leq k \leq M.$$

$$\begin{aligned} a_k(t) &= P(u_1, u_2, \dots, u_t, s_t = k) \\ &= \sum_{l=1}^M P(u_1, u_2, \dots, u_t, s_t = k, s_{t-1} = l) \\ &= \sum_{l=1}^M P(u_1, u_2, \dots, u_{t-1}, s_{t-1} = l) P(u_t, s_t = k \mid u_1, u_2, \dots, u_{t-1}, s_{t-1} = l) \\ &= \sum_{l=1}^M \alpha_l(t-1) P(u_t, s_t = k \mid s_{t-1} = l) \\ &= \sum_{l=1}^M \alpha_l(t-1) P(u_t \mid s_t = k, s_{t-1} = l) P(s_t = k \mid s_{t-1} = l) \\ &= \sum_{l=1}^M \alpha_l(t-1) P(u_t \mid s_t = k) P(s_t = k \mid s_{t-1} = l) \\ &= b_k(u_t) \sum_{l=1}^M \alpha_l(t-1) a_{l,k} \end{aligned}$$

- Define the **backward probability** $\beta_k(t)$ as the **conditional probability** of observing the data after time t , $u_i, i = t + 1, \dots, T$, given the state at time t is k .

$$\beta_k(t) = P(u_{t+1}, \dots, u_T \mid s_t = k) \quad 1 \leq t \leq T - 1$$

- Again, the backward probability can be computed by following recursive formula:

$$\beta_k(T) = 1$$

$$\beta_k(t) = \sum_{l=1}^M a_{k,l} b_l(u_{t+1}) \beta_l(t+1) \quad 1 \leq t < T$$

$$\begin{aligned}\beta_k(t) &= P(u_{t+1}, \dots, u_T \mid s_t = k) \\&= \sum_{l=1}^M P(u_{t+1}, \dots, u_T, s_{t+1} = l \mid s_t = k) \\&= \sum_{l=1}^M P(u_{t+1}, \dots, u_T \mid s_{t+1} = l, s_t = k) P(s_{t+1} = l \mid s_t = k) \\&= \sum_{l=1}^M P(u_{t+1}, \dots, u_T \mid s_{t+1} = l) a_{k,l} \\&= \sum_{l=1}^M P(u_{t+2}, \dots, u_T \mid s_{t+1} = l, u_{t+1}) P(u_{t+1} \mid s_{t+1} = l) a_{k,l} \\&= \sum_{l=1}^M P(u_{t+2}, \dots, u_T \mid s_{t+1} = l) b_l(u_{t+1}) a_{k,l} \\&= \sum_{l=1}^M a_{k,l} b_l(u_{t+1}) \beta_l(t+1)\end{aligned}$$

Compute $L_k(t)$ using forward and backward probabilities:

$$L_k(t) \equiv P(s_t = k \mid \mathbf{u}) = \frac{P(\mathbf{u}, s_t = k)}{P(\mathbf{u})} = \frac{\alpha_k(t) \beta_k(t)}{P(\mathbf{u})}$$

Proof:

$$\begin{aligned} P(\mathbf{u}, s_t = k) &= P(u_1, \dots, u_T, s_t = k) \\ &= P(u_1, \dots, u_t, s_t = k) P(u_{t+1}, \dots, u_T \mid u_1, \dots, u_t, s_t = k) \\ &= P(u_1, \dots, u_t, s_t = k) P(u_{t+1}, \dots, u_T \mid s_t = k) \\ &= \alpha_k(t) \beta_k(t) \end{aligned}$$

Compute $H_{k,l}(t)$ using forward and backward probabilities:

$$\begin{aligned} H_{k,l}(t) &= P(s_t = k, s_{t+1} = l | \mathbf{u}) = \frac{P(s_t = k, s_{t+1} = l, \mathbf{u})}{P(\mathbf{u})} \\ &= \frac{1}{P(\mathbf{u})} \alpha_k(t) a_{k,l} b_l(u_{t+1}) \beta_l(t+1) \end{aligned}$$

Proof:

$$\begin{aligned} P(s_t = k, s_{t+1} = l, \mathbf{u}) &= P(u_1, \dots, u_t, \dots, u_T, s_t = k, s_{t+1} = l) \\ &= P(u_1, \dots, u_t, s_t = k) P(u_{t+1}, s_{t+1} = l \mid s_t = k, u_1, \dots, u_t) \\ &\quad P(u_{t+2}, \dots, u_T \mid s_{t+1} = l, s_t = k, u_1, \dots, u_{t+1}) \\ &= \alpha_k(t) P(u_{t+1}, s_{t+1} = l \mid s_t = k) P(u_{t+2}, \dots, u_T \mid s_{t+1} = l) \\ &= \alpha_k(t) P(s_{t+1} = l \mid s_t = k) P(u_{t+1} \mid s_{t+1} = l, s_t = k) \beta_l(t+1) \\ &= \alpha_k(t) P(s_{t+1} = l \mid s_t = k) P(u_{t+1} \mid s_{t+1} = l) \beta_l(t+1) \\ &= \alpha_k(t) a_{k,l} b_l(u_{t+1}) \beta_l(t+1) \end{aligned}$$

The joint observed data likelihood is:

$$P(\mathbf{u}) = \sum_{k=1}^M \alpha_k(t) \beta_k(t)$$

Proof:

$$\begin{aligned} P(\mathbf{u}) &= \sum_{k=1}^M P(u_1, \dots, u_t, \dots, u_T, s_t = k) \\ &= \sum_{k=1}^M P(u_1, \dots, u_t, s_t = k) P(u_{t+1}, \dots, u_T \mid s_t = k, u_1, \dots, u_t) \\ &= \sum_{k=1}^M P(u_1, \dots, u_t, s_t = k) P(u_{t+1}, \dots, u_T \mid s_t = k) \\ &= \sum_{k=1}^M \alpha_k(t) \beta_k(t) \end{aligned}$$

To summarize, estimation of model parameters requires iterating following steps, under the current estimates of parameters:

1. Compute the forward and backward probabilities:

$$\alpha_k(1) = \pi_k b_k(u_1) \quad 1 \leq k \leq M$$

$$\alpha_k(t) = b_k(u_t) \sum_{l=1}^M \alpha_l(t-1) a_{l,k} \quad 1 < t \leq T, 1 \leq k \leq M.$$

$$\beta_k(T) = 1$$

$$\beta_k(t) = \sum_{l=1}^M a_{k,l} b_l(u_{t+1}) \beta_l(t+1) \quad 1 \leq t < T$$

2. Compute whole data likelihood: $P(\mathbf{u}) = \sum_{k=1}^M \alpha_k(t) \beta_k(t)$.
3. Compute $L_k(t)$ and $H_{k,l}(t)$ from forward/backward probabilities:

$$L_k(t) = \frac{\alpha_k(t) \beta_k(t)}{P(\mathbf{u})}$$
$$H_{k,l}(t) = \frac{1}{P(\mathbf{u})} \alpha_k(t) a_{k,l} b_l(u_{t+1}) \beta_l(t+1)$$

4. Update parameters using $L_k(t)$ and $H_{k,l}(t)$ (assuming Normal emission probabilities):

$$\mu_k = \frac{\sum_{t=1}^T L_k(t) u_t}{\sum_{t=1}^T L_k(t)}, \quad \sigma_k^2 = \frac{\sum_{t=1}^T L_k(t) (u_t - \mu_k)^2}{\sum_{t=1}^T L_k(t)},$$
$$a_{k,l} = \frac{\sum_{t=1}^{T-1} H_{k,l}(t)}{\sum_{t=1}^{T-1} L_k(t)}, \quad \pi_k = \frac{\sum_{t=1}^T L_k(t)}{T}$$

- HMM is used to model sequential data.
- Difference between HMM and mixture model: mixture model assumes iid observations, HMM assumes underlying sequential correlation among hidden states.
- Important components in a HMM: initial, emission and transition probabilities.
- Goals of HMM: estimate hidden states and model parameters, find best path, future prediction.
- Parameter estimation via EM and forward-backward algorithm.
- Next lecture: dynamic programming and Viterbi algorithm to find the best path.