Course 06: UKF

Sunday, November 3, 2019 10:16 PM

slam06-ukf

Robot Mapping

Unscented Kalman Filter

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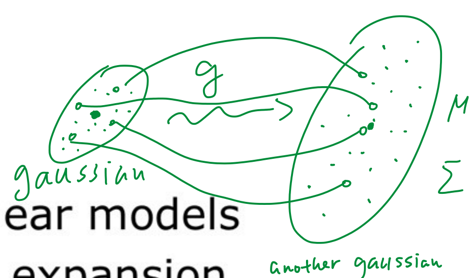
AIS Autonomous Intelligent Systems

KF, EKF and UKF



- Kalman filter requires linear models
- EKF linearizes via Taylor expansion

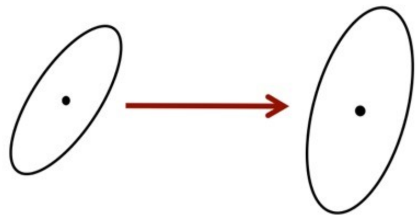
Is there a better way to linearize?

Unscented Transform

⬇

Unscented Kalman Filter (UKF)

Taylor Approximation (EKF)



Linearization of the non-linear function through Taylor expansion

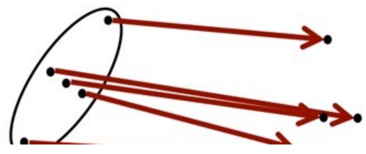
3

Unscented Transform

Compute a set of (so-called) sigma points

4

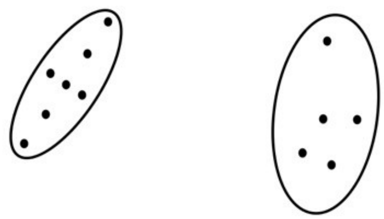
Unscented Transform



Transform each sigma point
through the non-linear function

5

Unscented Transform



Compute Gaussian from the
transformed and weighted
sigma points

6

Unscented Transform Overview

- Compute a set of sigma points
- Each sigma points has a weight
- Transform the point through the non-linear function
- Compute a Gaussian from weighted points

[Advantage]

- Avoids to linearize **around the mean** as Taylor expansion (and EKF) does

7

Sigma Points

- How to choose the sigma points?
- How to set the weights?

8

Sigma Points Properties

- How to choose the sigma points?
- How to set the weights?
- Select $\mathcal{X}^{[i]}, w^{[i]}$ so that:

$$\sum_i w^{[i]} = 1$$

$$\mu = \sum_i w^{[i]} \mathcal{X}^{[i]}$$

$$\Sigma = \sum_i w^{[i]} (\mathcal{X}^{[i]} - \mu)(\mathcal{X}^{[i]} - \mu)^T$$

- There is no unique solution for $\mathcal{X}^{[i]}, w^{[i]}$

An trivial practice:
choose Identity,
we should get EXACTLY
SAME DISTRIBUTION!

9

Sigma Points

- Choosing the sigma points

▪ Choosing the sigma points

$$\mathcal{X}^{[0]} = \mu$$

First sigma point is the mean

(1) number of sigma point to choose depends on the dim of the problem.
(2) Every time choose 2 extra sigma points if one more dim is added to the problem.
base is [1 dim ⇔ 3 sigma points].

10

Sigma Points

▪ Choosing the sigma points

$$\begin{aligned}
\mathcal{X}^{[0]} &= \mu \\
\mathcal{X}^{[i]} &= \mu + \left(\sqrt{(n+\lambda)\,\Sigma}\right)_i \quad \text{for } i = 1, \ldots, n \\
\mathcal{X}^{[i]} &= \mu - \left(\sqrt{(n+\lambda)\,\Sigma}\right)_{i-n} \quad \text{for } i = n+1, \ldots, 2n
\end{aligned}$$

matrix square root

column vector

dimensionality

scaling parameter

↳ tells us how far do we want move away from the mean. @ certain direction.
* Larger → further.

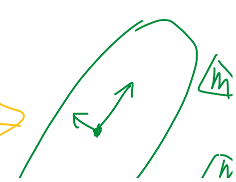
11

Matrix Square Root

▪ Defined as S with $\Sigma = SS$ ↷ Definition of matrix square root
▪ Computed via diagonalization

$$\begin{aligned}
\Sigma &= VDV^{-1} \\
&= V \begin{pmatrix} d_{11} & \cdots & 0 \\ 0 & \ddots & 0 \\ 0 & \cdots & d_{nn} \end{pmatrix} V^{-1}
\end{aligned}$$

eigenvalues of the matrix



$$= V \begin{pmatrix} \sqrt{d_{11}} & \dots & 0 \\ 0 & \ddots & 0 \\ 0 & \dots & \sqrt{d_{nn}} \end{pmatrix} \begin{pmatrix} \sqrt{d_{11}} & \dots & 0 \\ 0 & \ddots & 0 \\ 0 & \dots & \sqrt{d_{nn}} \end{pmatrix} V^{-1}$$

12

Matrix Square Root

- Thus, we can define $S = V D^{1/2} V^{-1}$

$$S = V \underbrace{\begin{pmatrix} \sqrt{d_{11}} & \dots & 0 \\ 0 & \ddots & 0 \\ 0 & \dots & \sqrt{d_{nn}} \end{pmatrix}}_{D^{1/2}} V^{-1}$$

- so that

$$SS = (VD^{1/2}V^{-1})(VD^{1/2}V^{-1}) = VDV^{-1} = \Sigma$$

13

Cholesky Matrix Square Root

- Alternative definition of the matrix square root

$$L \text{ with } \Sigma = LL^T$$

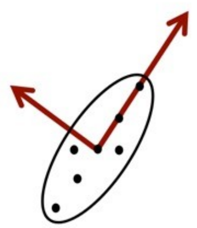
- Result of the Cholesky decomposition
- Numerically stable solution
- Often used in UKF implementations more pratically easier to
- L and Σ have the same Eigenvectors

14

Sigma Points and Eigenvectors

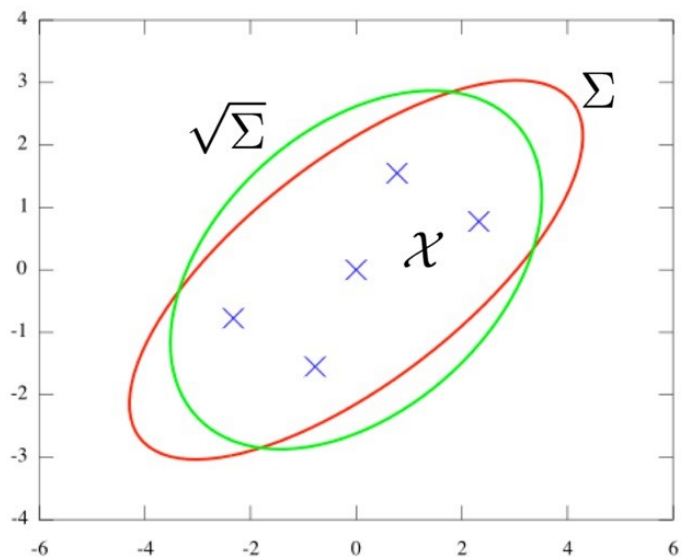
- Sigma point **can** but **do not have to** lie on the main axes of Σ

$$\mathcal{X}^{[i]} = \mu + \left(\sqrt{(n+\lambda)\,\Sigma}\right)_i \quad \text{for } i = 1, \ldots, n$$
$$\mathcal{X}^{[i]} = \mu - \left(\sqrt{(n+\lambda)\,\Sigma}\right)_{i-n} \quad \text{for } i = n+1, \ldots, 2n$$



15

Sigma Points Example



16

Sigma Point Weights

- Weight sigma points

for computing the mean

parameters

λ

$$w_m^{[0]} = \frac{\lambda}{n+\lambda}$$
$$w_c^{[0]} = w_m^{[0]} + (1 - \alpha^2 + \beta)$$
$$w_m^{[i]} = w_c^{[i]} = \frac{1}{2(n+\lambda)} \quad \text{for } i = 1, \ldots, 2n$$

for computing the covariance

17

Recover the Gaussian

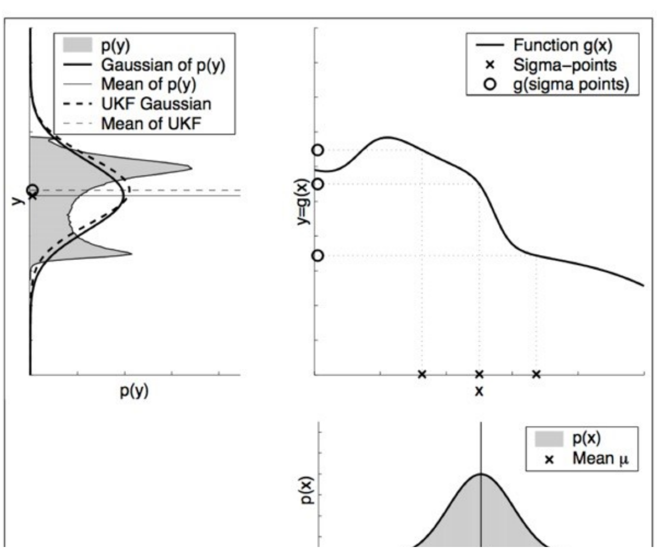
- Compute Gaussian from weighted and transformed points

$$\mu' = \sum_{i=0}^{2n} w_m^{[i]}\, g(\mathcal{X}^{[i]})$$
$$\Sigma' = \sum_{i=0}^{2n} w_c^{[i]}\, (g(\mathcal{X}^{[i]}) - \mu')(g(\mathcal{X}^{[i]}) - \mu')^T$$

18

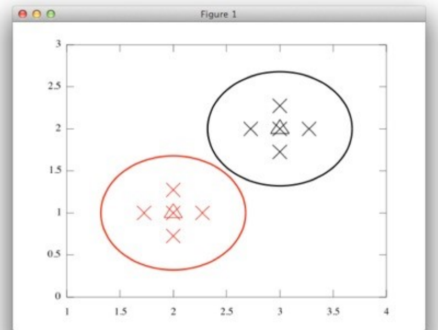
Example

We want the best possible gaussian distribution

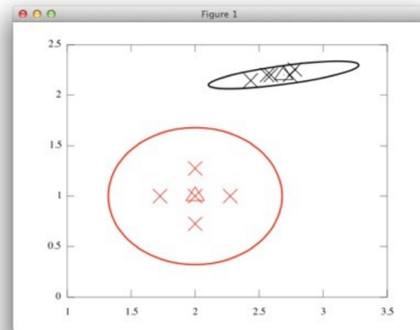


19

Examples



$$g((x,y)^T) = \begin{pmatrix} x+1 \\ y+1 \end{pmatrix}^T$$



$$g((x,y)^T) = \begin{pmatrix} 1 + x + \sin(2x) + \cos(y) \\ 2 + 0.2y \end{pmatrix}^T$$

20

Unscented Transform Summary

- Sigma points

$$\begin{aligned} \mathcal{X}^{[0]} &= \mu \\ \mathcal{X}^{[i]} &= \mu + \left(\sqrt{(n+\lambda)\,\Sigma}\right)_i \quad \text{for } i = 1, \ldots, n \\ \mathcal{X}^{[i]} &= \mu - \left(\sqrt{(n+\lambda)\,\Sigma}\right)_{i-n} \quad \text{for } i = n+1, \ldots, 2n \end{aligned}$$

- Weights

$$\begin{aligned} w_m^{[0]} &= \frac{\lambda}{n+\lambda} \\ w_c^{[0]} &= w_m^{[0]} + (1 - \alpha^2 + \beta) \\ w_m^{[i]} = w_c^{[i]} &= \frac{1}{2(n+\lambda)} \quad \text{for } i = 1, \ldots, 2n \end{aligned}$$

21

UT Parameters

- Free parameters as there is no unique

Free parameters as there is no unique solution

- Scaled Unscented Transform suggests

$$
\begin{aligned}
\kappa &\geq 0 \\
\alpha &\in (0,1] \\
\lambda &= \alpha^2(n+\kappa) - n \\
\beta &= 2
\end{aligned}
$$

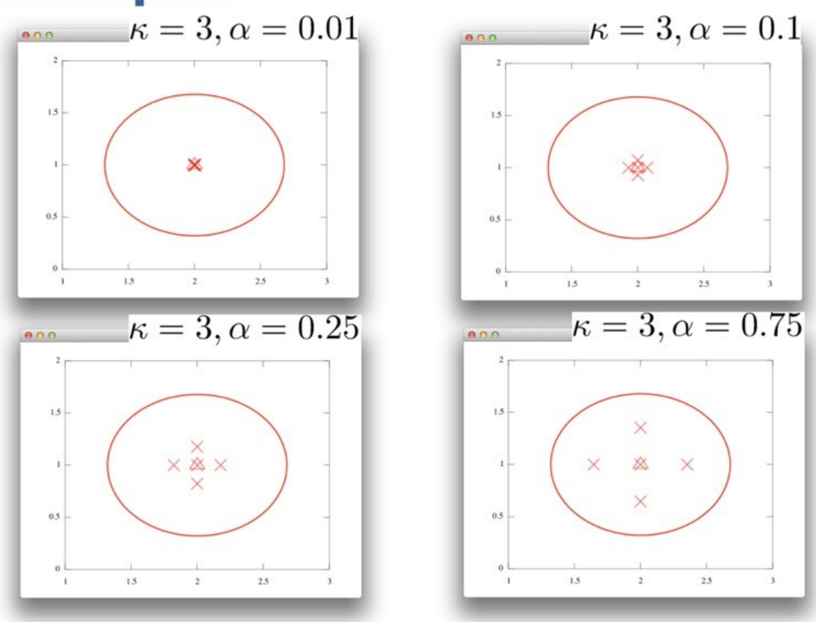
Influence how far the sigma points are away from the mean

Optimal choice for Gaussians

↳ other situations, depends on the special case.

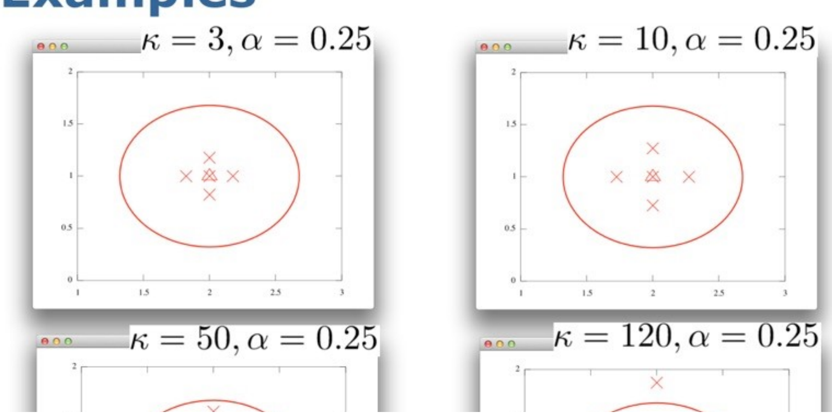
22

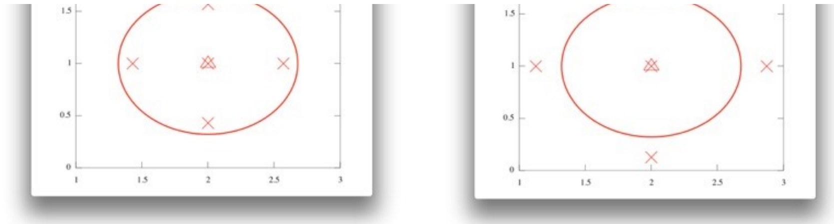
Examples



23

Examples





24

EKF Algorithm

$$\textbf{Extended\_Kalman\_filter}(\mu_{t-1}, \Sigma_{t-1}, u_t, z_t)\textbf{:}$$

$$\bar{\mu}_t = g(u_t, \mu_{t-1})$$
$$\bar{\Sigma}_t = G_t\, \Sigma_{t-1}\, G_t^T + R_t$$

$$K_t = \bar{\Sigma}_t\, H_t^T (H_t\, \bar{\Sigma}_t\, H_t^T + Q_t)^{-1}$$
$$\mu_t = \bar{\mu}_t + K_t(z_t - h(\bar{\mu}_t))$$
$$\Sigma_t = (I - K_t\, H_t)\, \bar{\Sigma}_t$$
$$\text{return } \mu_t, \Sigma_t$$

25

EKF to UKF – Prediction

Unscented

$$\textbf{\cancel{Extended}\_Kalman\_filter}(\mu_{t-1}, \Sigma_{t-1}, u_t, z_t)\textbf{:}$$

$\bar{\mu}_t =$ replace this by sigma point
$\bar{\Sigma}_t =$ propagation of the motion

$$K_t = \bar{\Sigma}_t\, H_t^T (H_t\, \bar{\Sigma}_t\, H_t^T + Q_t)^{-1}$$
$$\mu_t = \bar{\mu}_t + K_t(z_t - h(\bar{\mu}_t))$$
$$\Sigma_t = (I - K_t\, H_t)\, \bar{\Sigma}_t$$
$$\text{return } \mu_t, \Sigma_t$$

(1) get sigma points : $\mathcal{X}_i$
(2) apply nonlinear func :

26

UKF Algorithm – Prediction

1: **Unscented_Kalman_filter**$(\mu_{t-1}, \Sigma_{t-1}, u_t, z_t)$**:**

2: $\mathcal{X}_{t-1} = (\mu_{t-1} \quad \mu_{t-1} + \sqrt{(n+\lambda)\Sigma_{t-1}} \quad \mu_{t-1} - \sqrt{(n+\lambda)\Sigma_{t-1}})$

3: $\bar{\mathcal{X}}_t^* = g(u_t, \mathcal{X}_{t-1})$

4: $\bar{\mu}_t = \sum_{i=0}^{2n} w_m^{[i]} \bar{\mathcal{X}}_t^{*[i]}$

5: $\bar{\Sigma}_t = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{X}}_t^{*[i]} - \bar{\mu}_t)(\bar{\mathcal{X}}_t^{*[i]} - \bar{\mu}_t)^T + R_t$

27

EKF to UKF – Correction

Unscented

1: ~~**Extended**~~**_Kalman_filter**$(\mu_{t-1}, \Sigma_{t-1}, u_t, z_t)$**:**

2: $\bar{\mu}_t =$ replace this by sigma point

3: $\bar{\Sigma}_t =$ propagation of the motion

use sigma point propagation for the expected observation and Kalman gain

5: $\mu_t = \bar{\mu}_t + K_t(z_t - \hat{z}_t)$

6: $\Sigma_t = \bar{\Sigma}_t - K_t\, S_t\, K_t^T$

7: *return* μ_t, Σ_t

28

UKF Algorithm – Correction (1)

6: $\bar{\mathcal{X}}_t = (\bar{\mu}_t \quad \bar{\mu}_t + \sqrt{(n+\lambda)\bar{\Sigma}_t} \quad \bar{\mu}_t - \sqrt{(n+\lambda)\bar{\Sigma}_t})$

7: $\bar{\mathcal{Z}}_t = h(\bar{\mathcal{X}}_t)$

8: $\hat{z}_t = \sum_{i=0}^{2n} w_m^{[i]} \bar{\mathcal{Z}}_t^{[i]}$

$$S_t = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)(\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)^T + Q_t$$

$$\bar{\Sigma}_t^{x,z} = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{X}}_t^{[i]} - \bar{\mu}_t)(\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)^T$$

$$K_t = \bar{\Sigma}_t^{x,z} \, S_t^{-1}$$

formula looks like different than EKF.
(But it's still the same thing).

UKF Algorithm – Correction (1)

$$\bar{\mathcal{X}}_t = (\bar{\mu}_t \quad \bar{\mu}_t + \sqrt{(n+\lambda)\bar{\Sigma}_t} \quad \bar{\mu}_t - \sqrt{(n+\lambda)\bar{\Sigma}_t})$$

$$\bar{\mathcal{Z}}_t = h(\bar{\mathcal{X}}_t)$$

$$\hat{z}_t = \sum_{i=0}^{2n} w_m^{[i]} \bar{\mathcal{Z}}_t^{[i]}$$

$$S_t = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)(\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)^T + Q_t$$

$$\bar{\Sigma}_t^{x,z} = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{X}}_t^{[i]} - \bar{\mu}_t)(\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)^T$$

$$K_t = \bar{\Sigma}_t^{x,z} \, S_t^{-1}$$

$$K_t = \overbrace{\bar{\Sigma}_t \, H_t^T}^{\bar{\Sigma}_t^{x,z}} \overbrace{(H_t \, \bar{\Sigma}_t \, H_t^T + Q_t)}^{S_t}{}^{-1}$$

(from EKF)

UKF Algorithm – Correction (2)

$$\bar{\mathcal{X}}_t = (\bar{\mu}_t \quad \bar{\mu}_t + \sqrt{(n+\lambda)\bar{\Sigma}_t} \quad \bar{\mu}_t - \sqrt{(n+\lambda)\bar{\Sigma}_t})$$

$$\bar{\mathcal{Z}}_t = h(\bar{\mathcal{X}}_t)$$

$$\hat{z}_t = \sum_{i=0}^{2n} w_m^{[i]} \bar{\mathcal{Z}}_t^{[i]}$$

$$S_t = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)(\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)^T + Q_t$$

$$\bar{\Sigma}_t^{x,z} = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{X}}_t^{[i]} - \bar{\mu}_t)(\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)^T$$

$$K_t = \bar{\Sigma}_t^{x,z} \, S_t^{-1}$$

$$\mu_t = \bar{\mu}_t + K_t(z_t - \hat{z}_t)$$

$$\Sigma_t = \bar{\Sigma}_t - K_t \, S_t \, K_t^T$$

return μ_t, Σ_t

31

UKF Algorithm – Correction (2)

$$\bar{\mathcal{X}}_t = (\bar{\mu}_t \quad \bar{\mu}_t + \sqrt{(n+\lambda)\bar{\Sigma}_t} \quad \bar{\mu}_t - \sqrt{(n+\lambda)\bar{\Sigma}_t})$$
$$\bar{\mathcal{Z}}_t = h(\bar{\mathcal{X}}_t)$$
$$\hat{z}_t = \sum_{i=0}^{2n} w_m^{[i]} \bar{\mathcal{Z}}_t^{[i]}$$
$$S_t = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)(\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)^T + Q_t$$
$$\bar{\Sigma}_t^{x,z} = \sum_{i=0}^{2n} w_c^{[i]} (\bar{\mathcal{X}}_t^{[i]} - \bar{\mu}_t)(\bar{\mathcal{Z}}_t^{[i]} - \hat{z}_t)^T$$
$$K_t = \bar{\Sigma}_t^{x,z} \; S_t^{-1}$$
$$\mu_t = \bar{\mu}_t + K_t(z_t - \hat{z}_t)$$
$$\Sigma_t = \bar{\Sigma}_t - K_t \; S_t \; K_t^T$$
$$\text{return } \mu_t, \Sigma_t$$

$$\begin{aligned} \Sigma_t &= (I - K_t H_t)\bar{\Sigma}_t \\ &= \bar{\Sigma}_t - K_t H_t \bar{\Sigma}_t \\ &= \bar{\Sigma}_t - K_t \left(\Sigma^{x,z}\right)^T \\ &= \bar{\Sigma}_t - K_t \left(\Sigma^{x,z} s_t^{-1} S_t\right)^T \\ &= \bar{\Sigma}_t - K_t \left(K_t S_t\right)^T \\ &= \bar{\Sigma}_t - K_t S_t^T K_t^T \\ &= \bar{\Sigma}_t - K_t S_t K_t^T \end{aligned}$$

(see next slide)

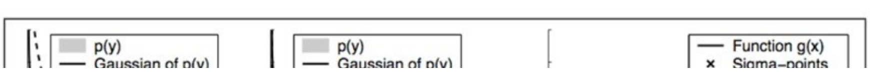
32

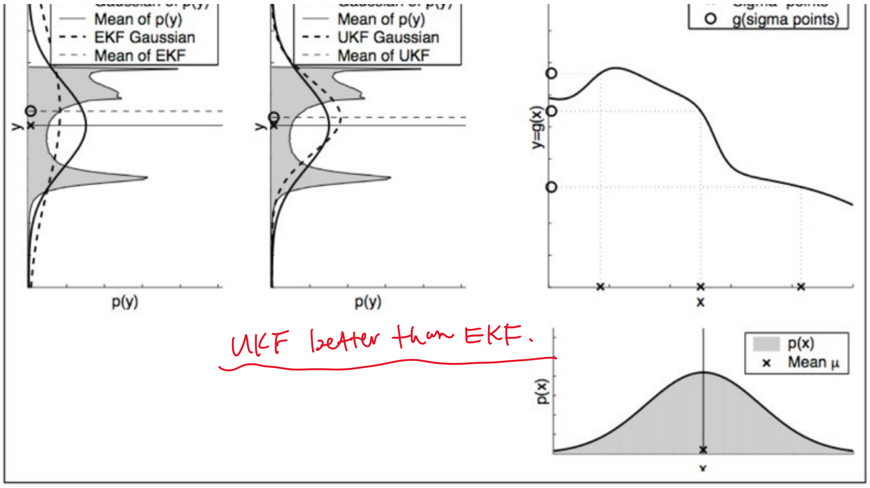
From EKF to UKF – Computing the Covariance

$$\begin{aligned} \Sigma_t &= (I - K_t H_t)\bar{\Sigma}_t \\ &= \bar{\Sigma}_t - K_t \underline{H_t \bar{\Sigma}_t} \\ &= \bar{\Sigma}_t - K_t \left(\bar{\Sigma}^{x,z}\right)^T \\ &= \bar{\Sigma}_t - K_t \left(\underline{\bar{\Sigma}^{x,z} S_t^{-1}} S_t\right)^T \\ &= \bar{\Sigma}_t - K_t \left(K_t S_t\right)^T \\ &= \bar{\Sigma}_t - K_t S_t^T K_t^T \\ &= \bar{\Sigma}_t - K_t S_t K_t^T \end{aligned}$$

33

UKF vs. EKF

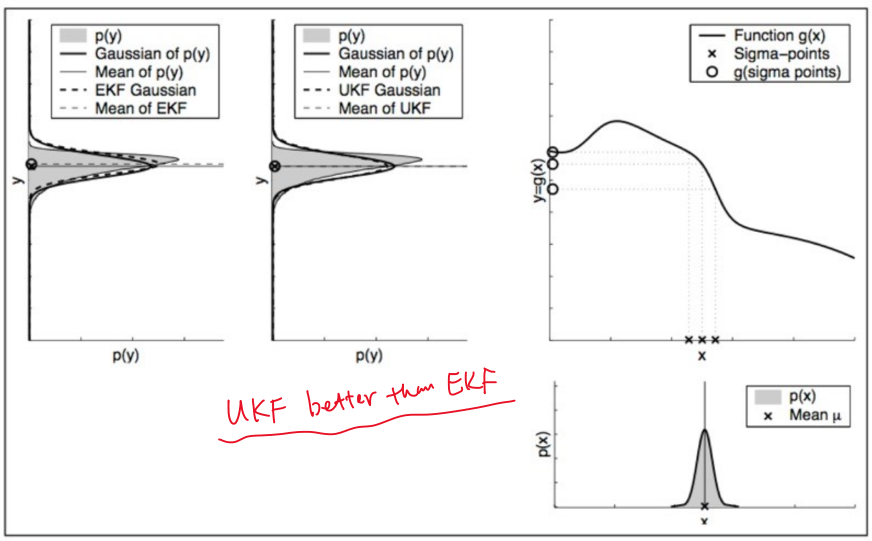




UKF better than EKF.

34

UKF vs. EKF (Small Covariance)



UKF better than EKF

35

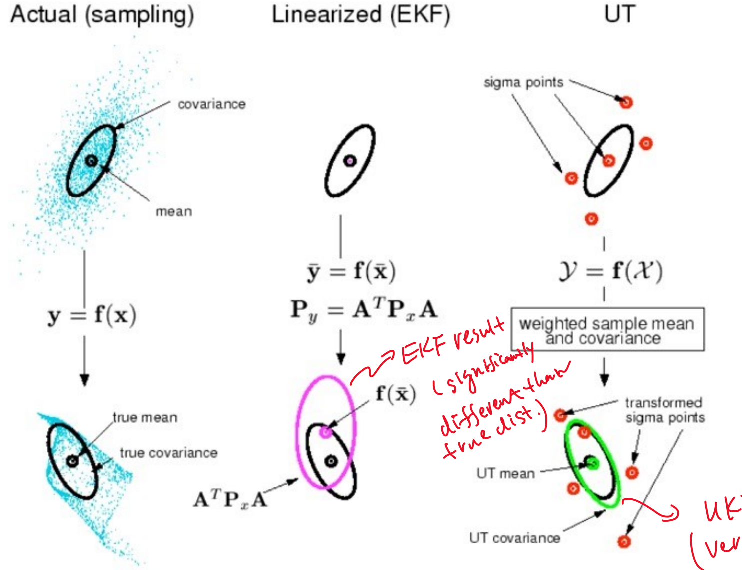
UKF vs. EKF – Banana Shape

EKF approximation

UKF approximation

36

UKF vs. EKF



EKF result (significantly different than true dist.)

UKF result. (very similar to true results)

Courtesy: E.A. Wan and R. van der Merwe

37

UT/UKF Summary

- Unscented transforms as an alternative to linearization
- UT is a better approximation than Taylor expansion (especially @ highly nonlinear functions)
- UT uses sigma point propagation
- Free parameters in UT
- UKF uses the UT in the prediction and correction step

38

UKF vs. EKF

- Same results as EKF for linear models
- Better approximation than EKF for non-linear models
- Differences often "somewhat small"
- No Jacobians needed for the UKF
- Same complexity class
- Slightly slower than the EKF
- Still restricted to Gaussian distributions

just better distribution than EKF of Taylor Expension (@1st order)

39

Literature

Unscented Transform and UKF

- Thrun et al.: "Probabilistic Robotics", Chapter 3.4
- "A New Extension of the Kalman Filter to Nonlinear Systems" by Julier and Uhlmann, 1995
- "Dynamische Zustandsschätzung" by Fränken, 2006, pages 31-34

40