

Improving Carter & Winn likelihood

In progress

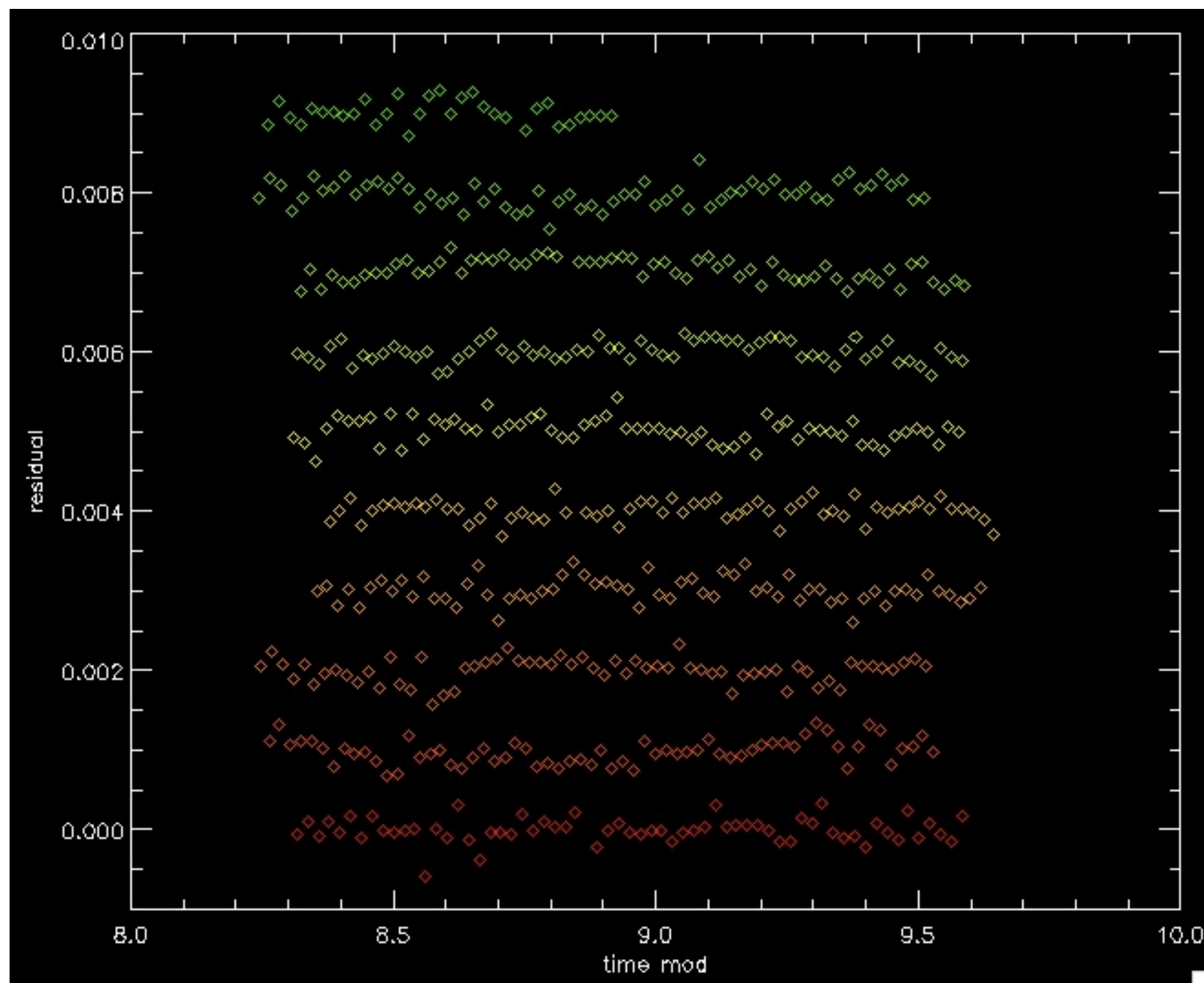
Bekki Dawson

- Carter & Winn likelihood assumes a combination of white noise and $1/f$ noise
- Carter: If there's another type of noise, the likelihood model will try to absorb it, potentially making the uncertainties in the parameters too large
- Carter advised me to detrend before fitting because wavelet likelihood is not good for certain noise

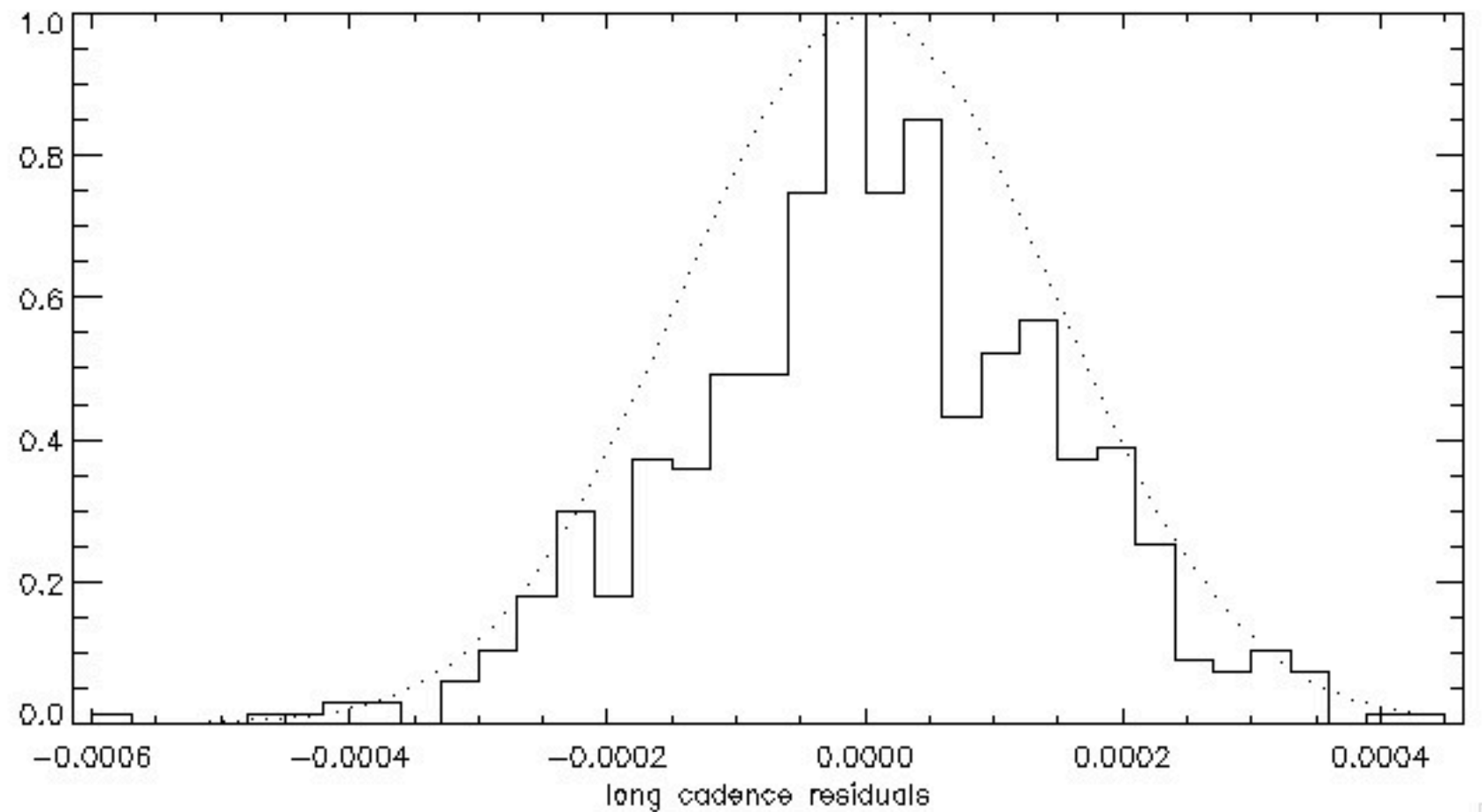
Example: KOI 1474

- Start by detrending with median filter and linear fit (masking the transit); linear fit becomes part of light curve model (fit via MCMC)
- Red and white noise amplitude are also part of model (use different for short and long cadence data)
- After getting transit times from light curve fit, separately fit dynamical model

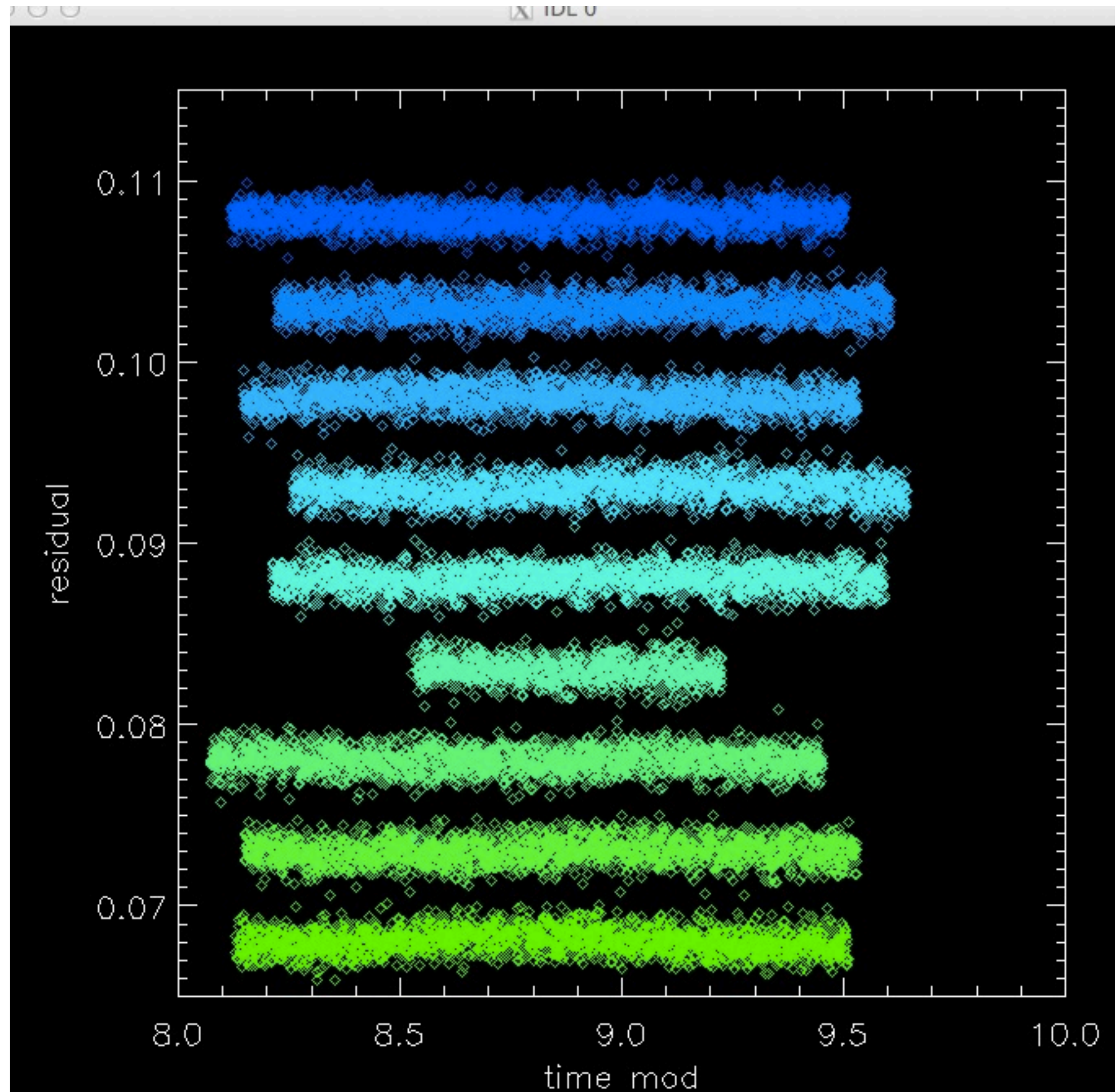
KOI
1474
light
curve
residuals
long
cadence

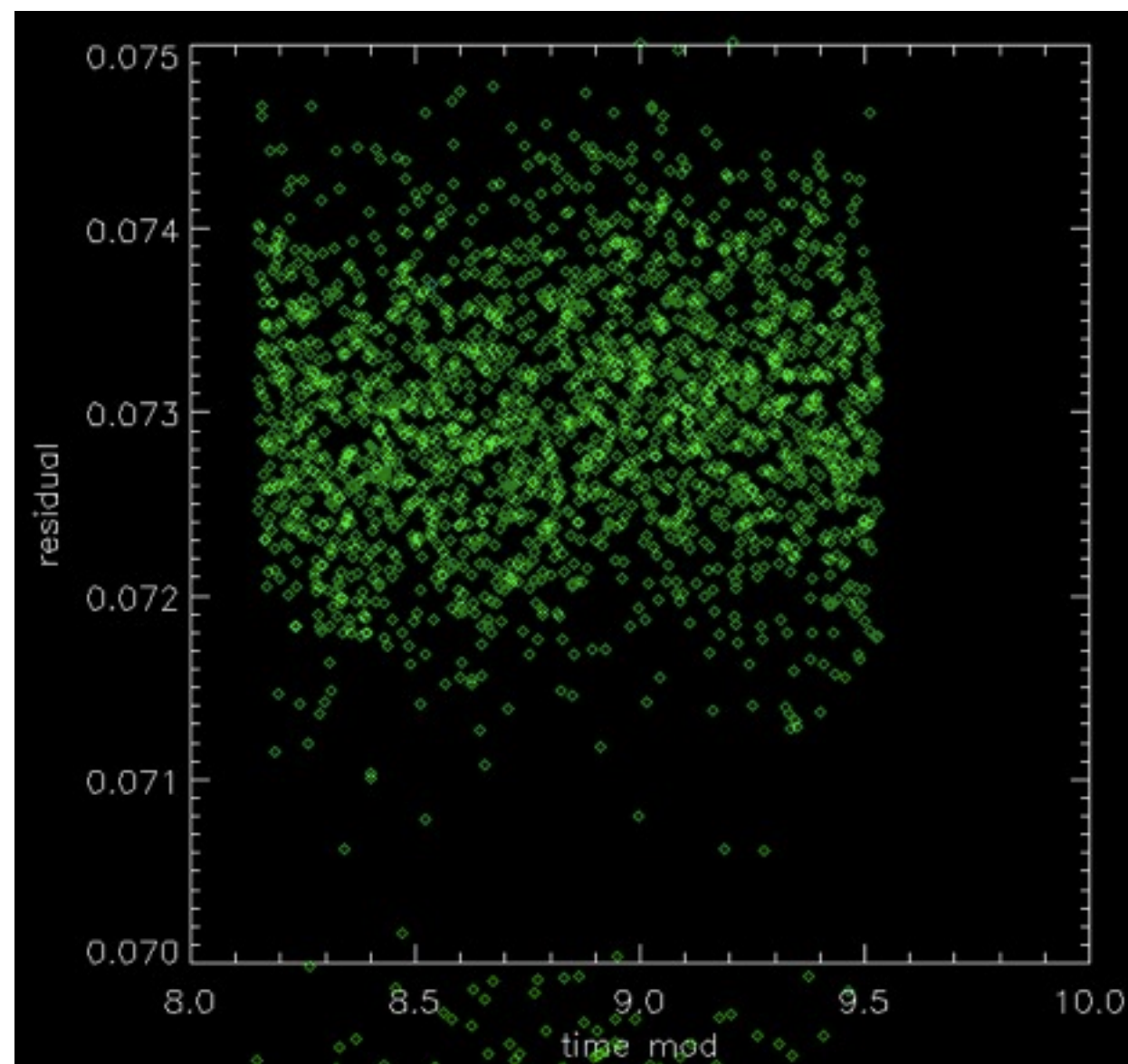
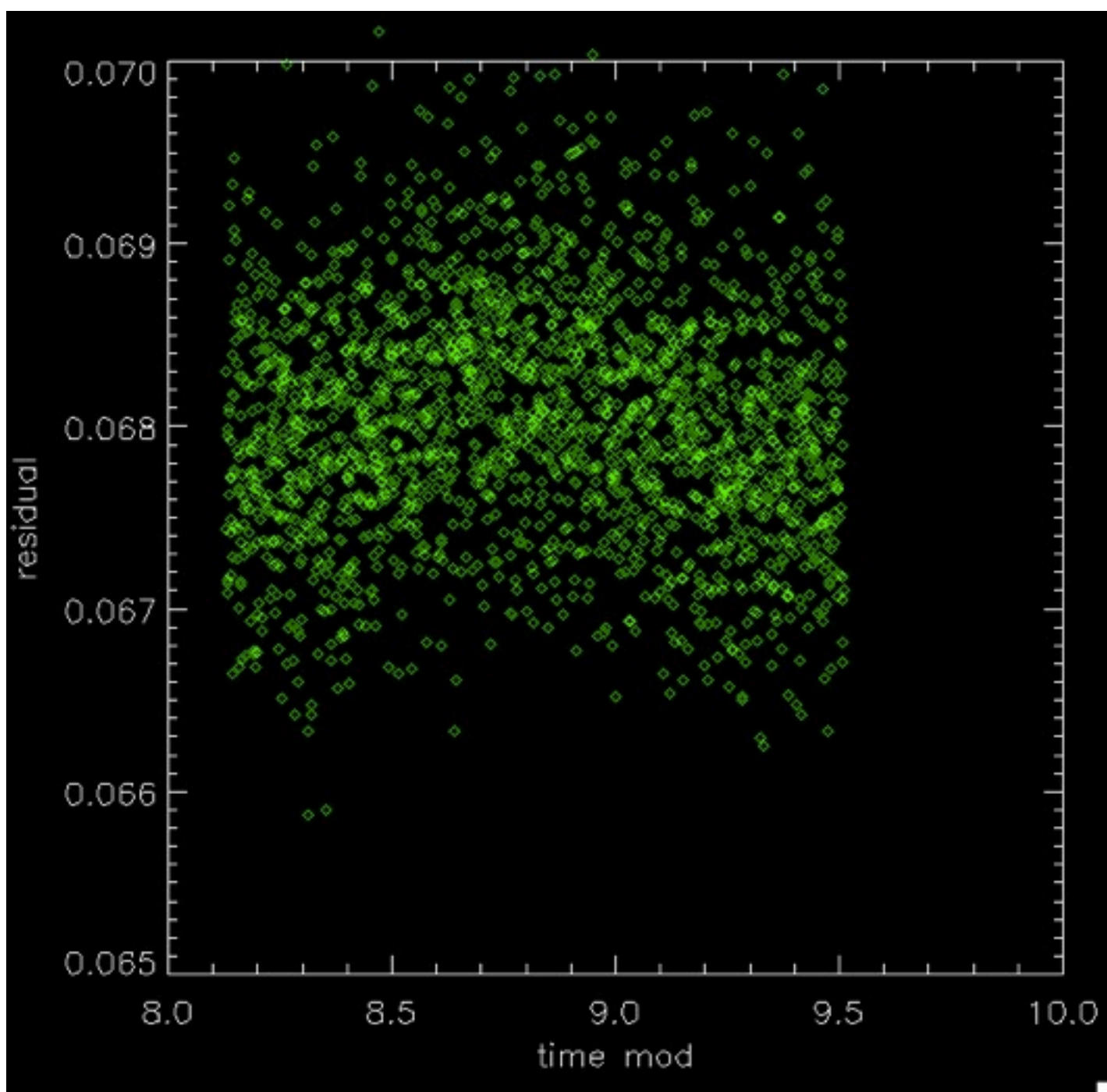


long cadence residuals

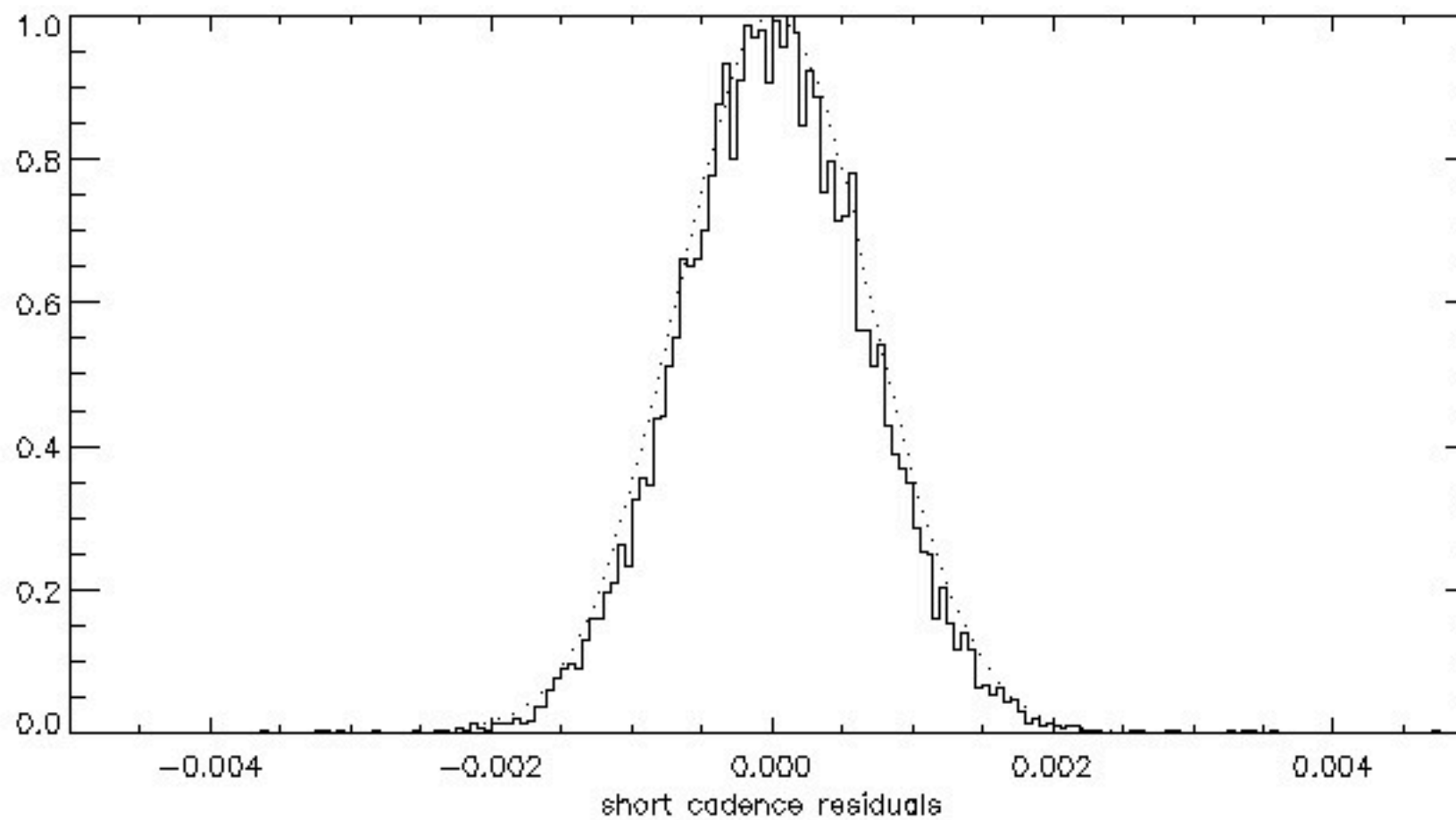


KOI
1474
light
curve
residuals
short
cadence

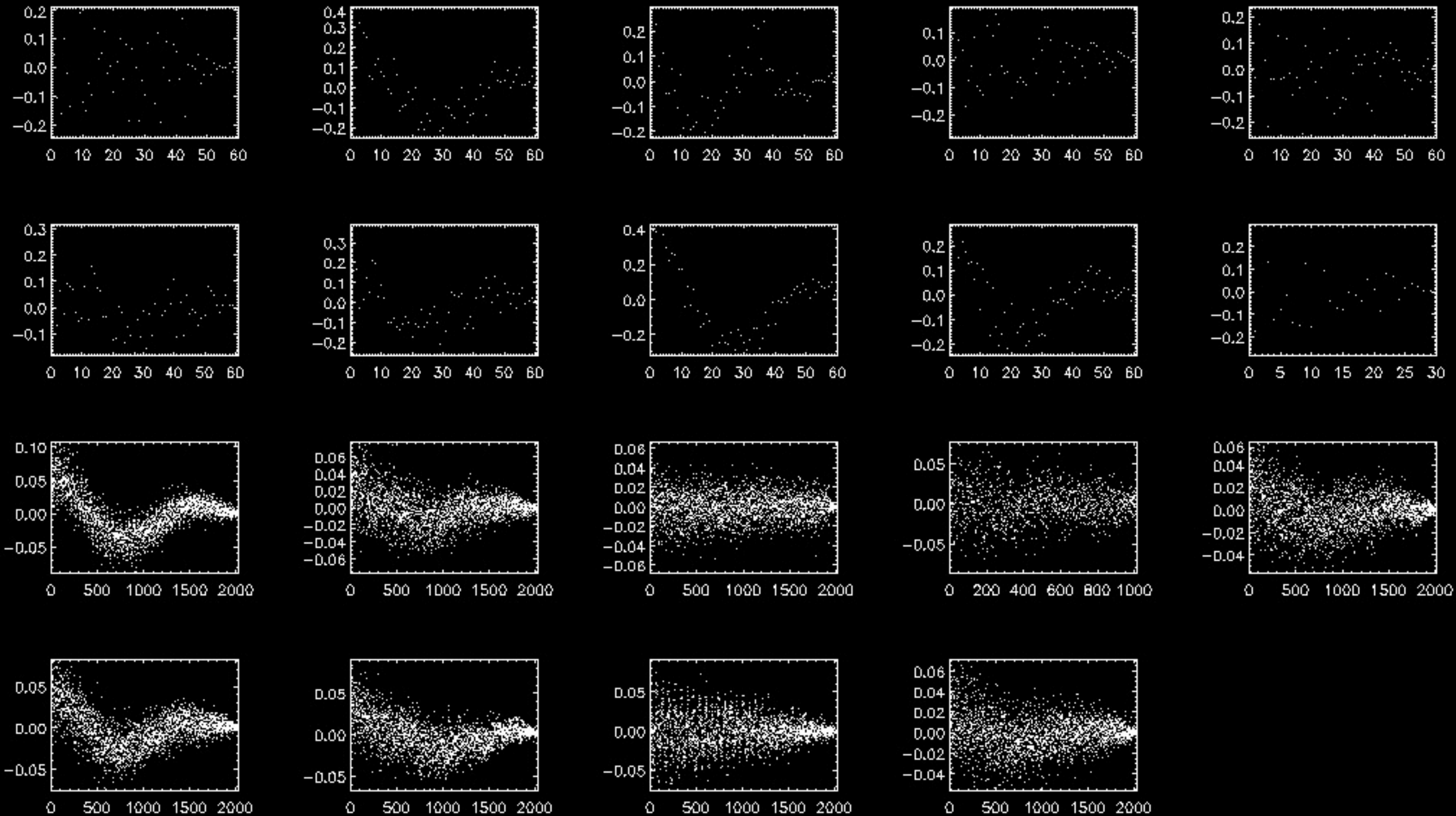




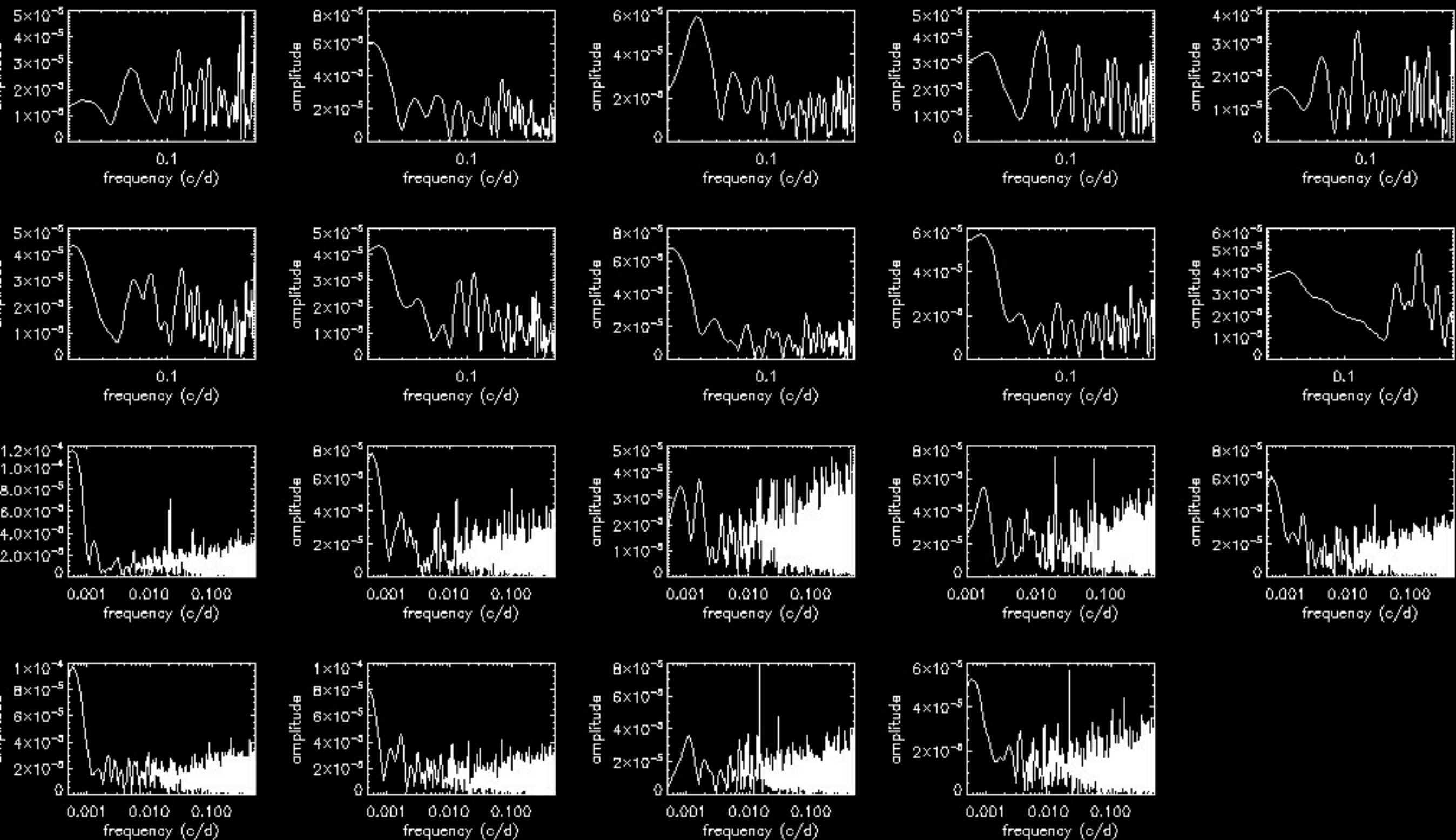
short cadence residuals



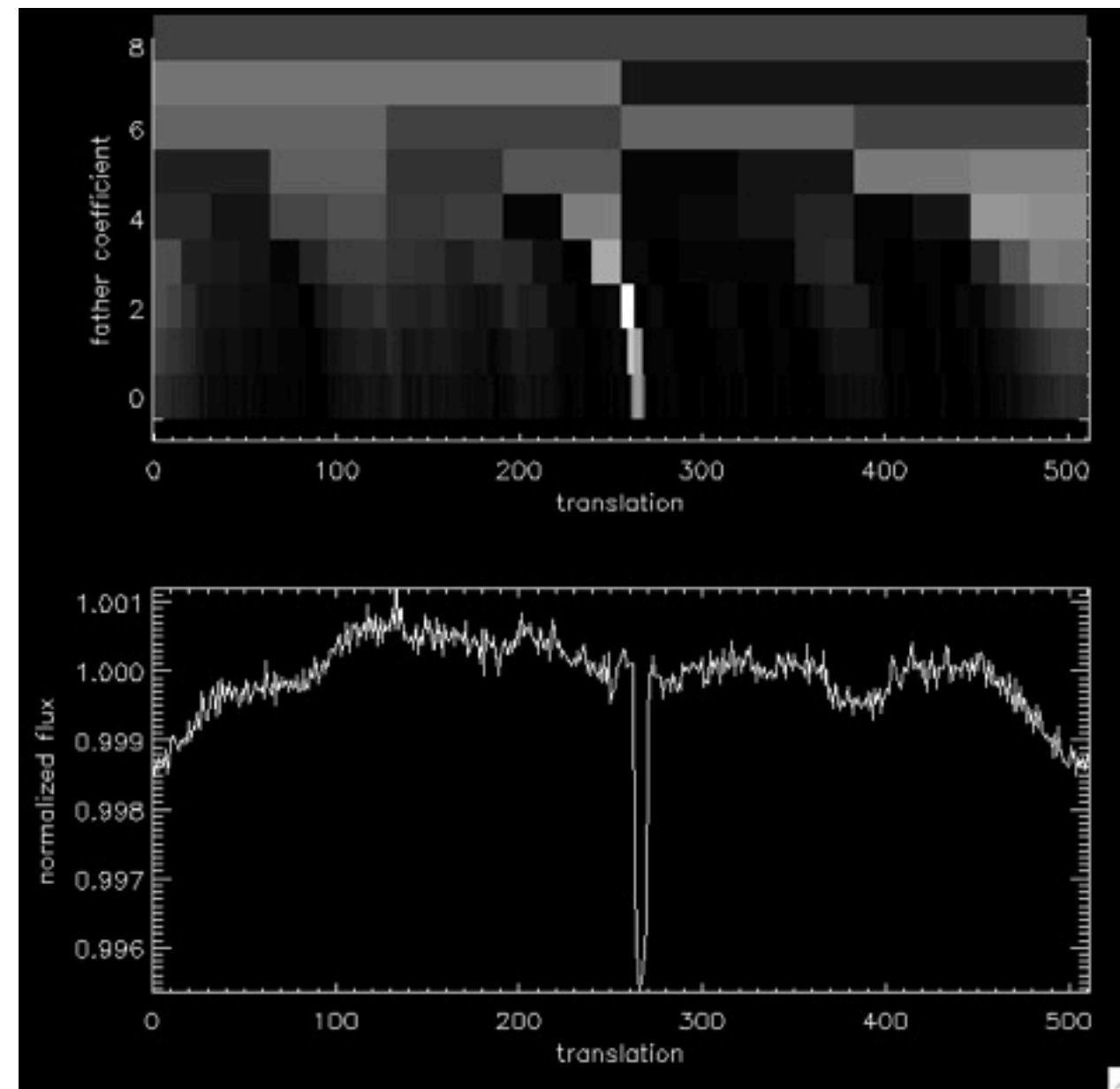
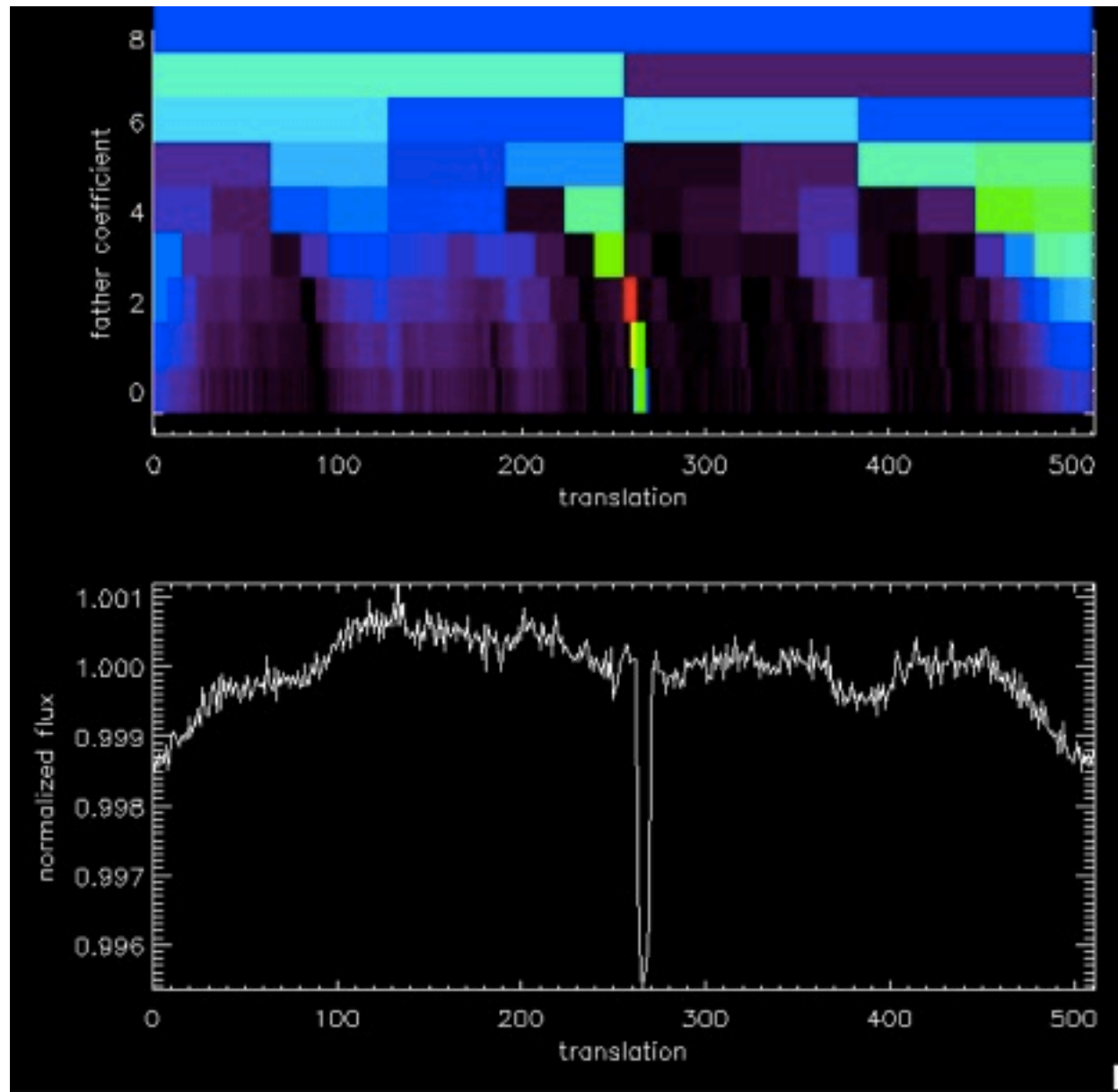
Auto-correlation



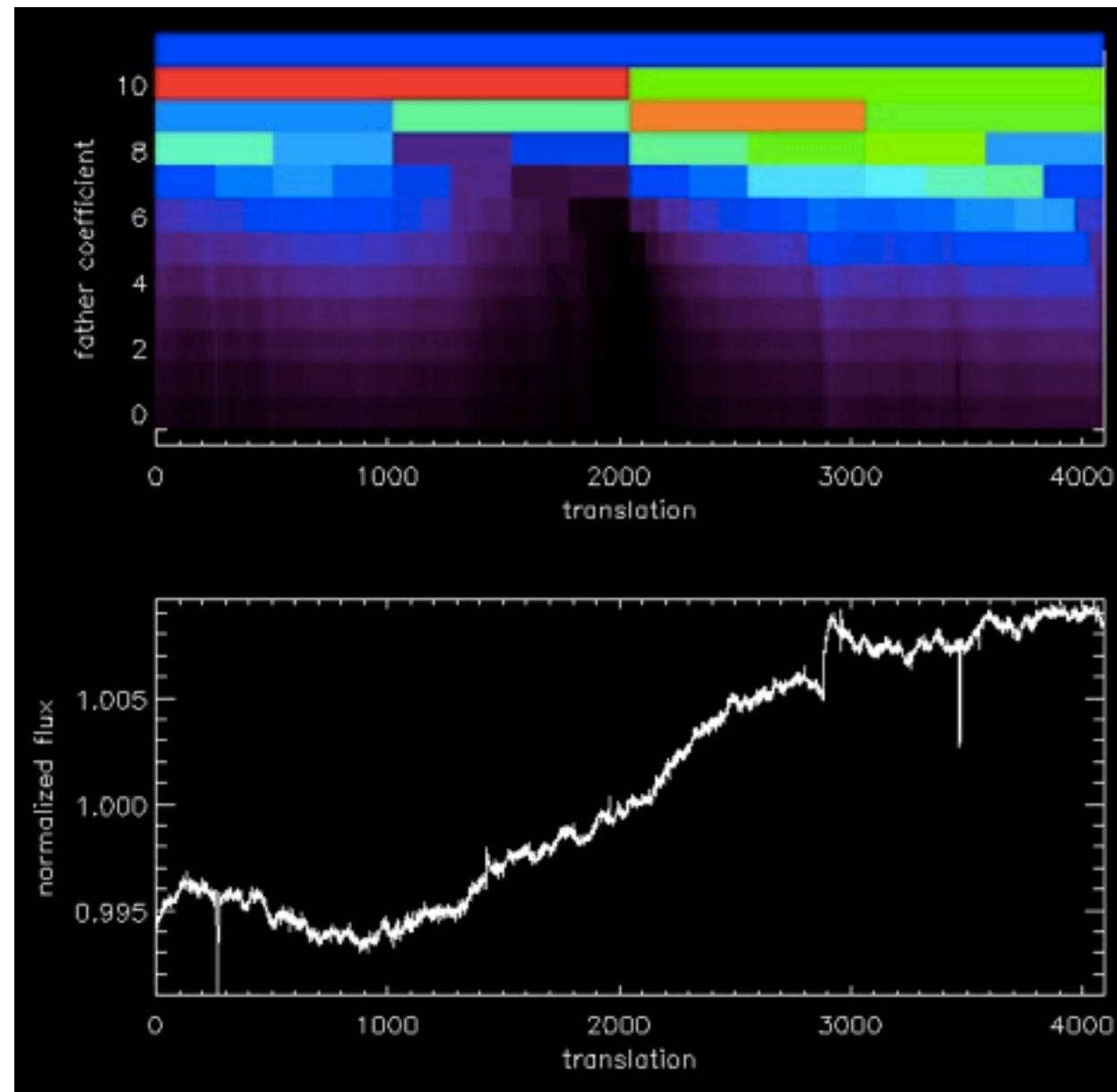
FFT



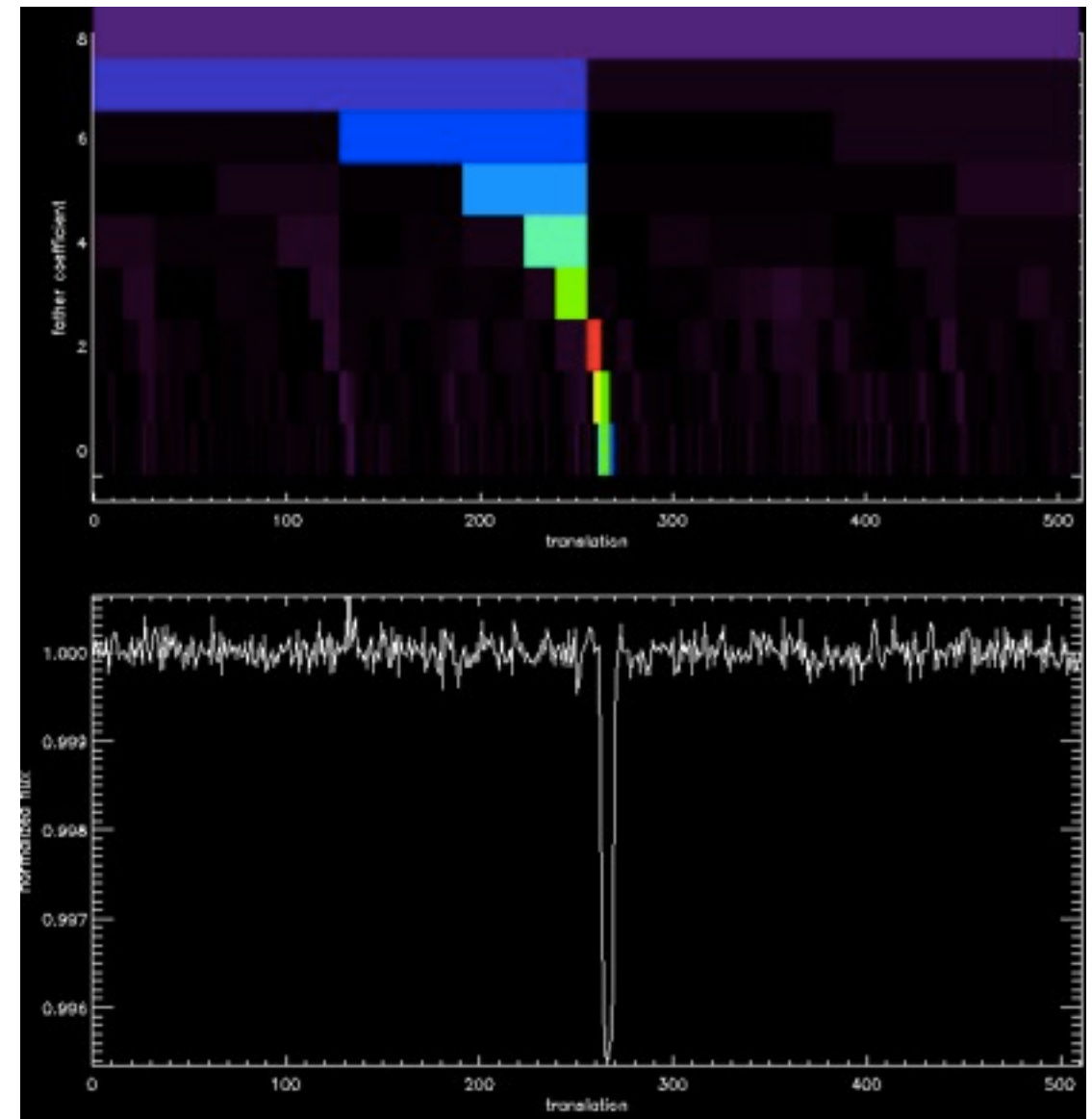
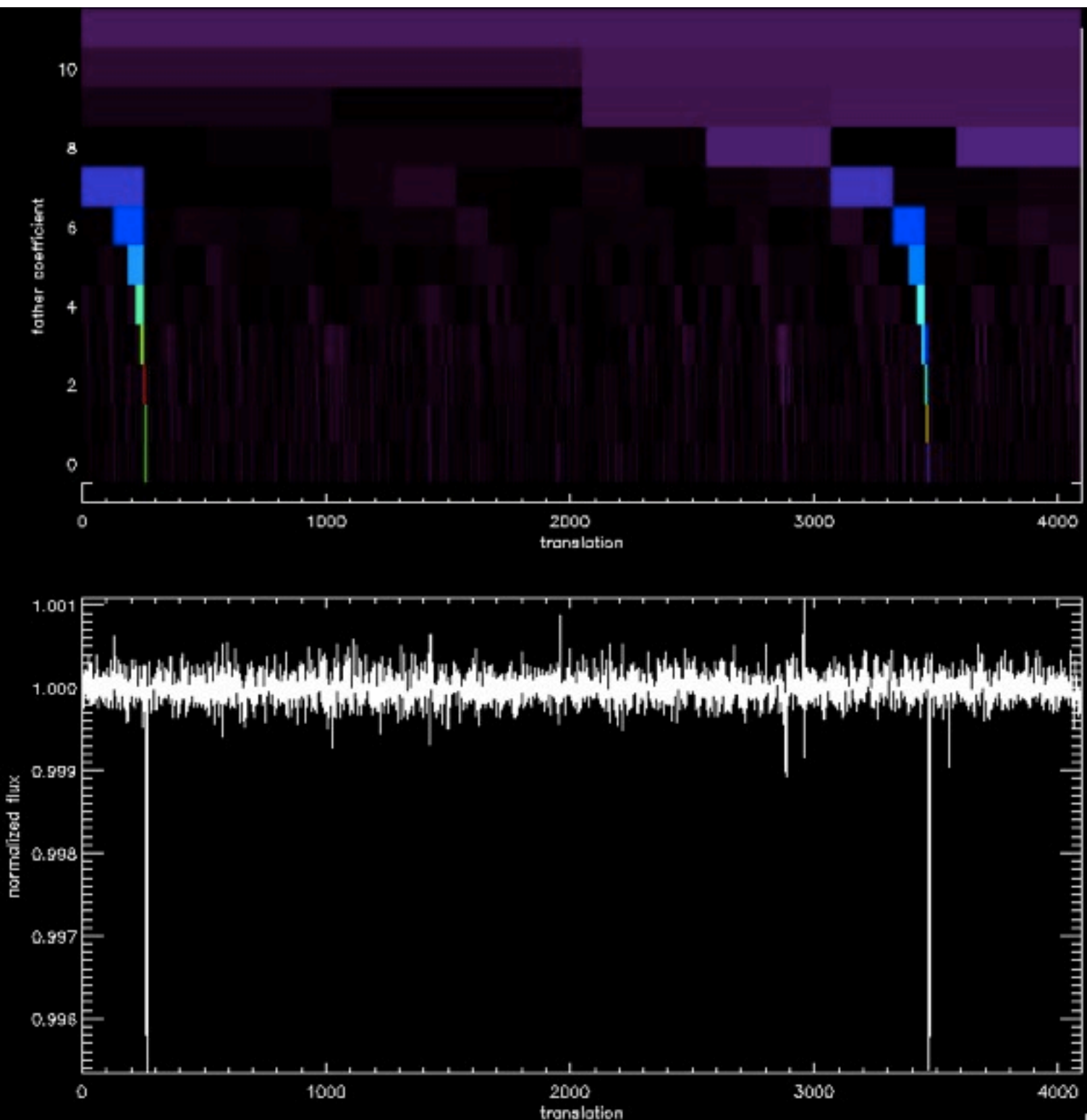
Wavelet



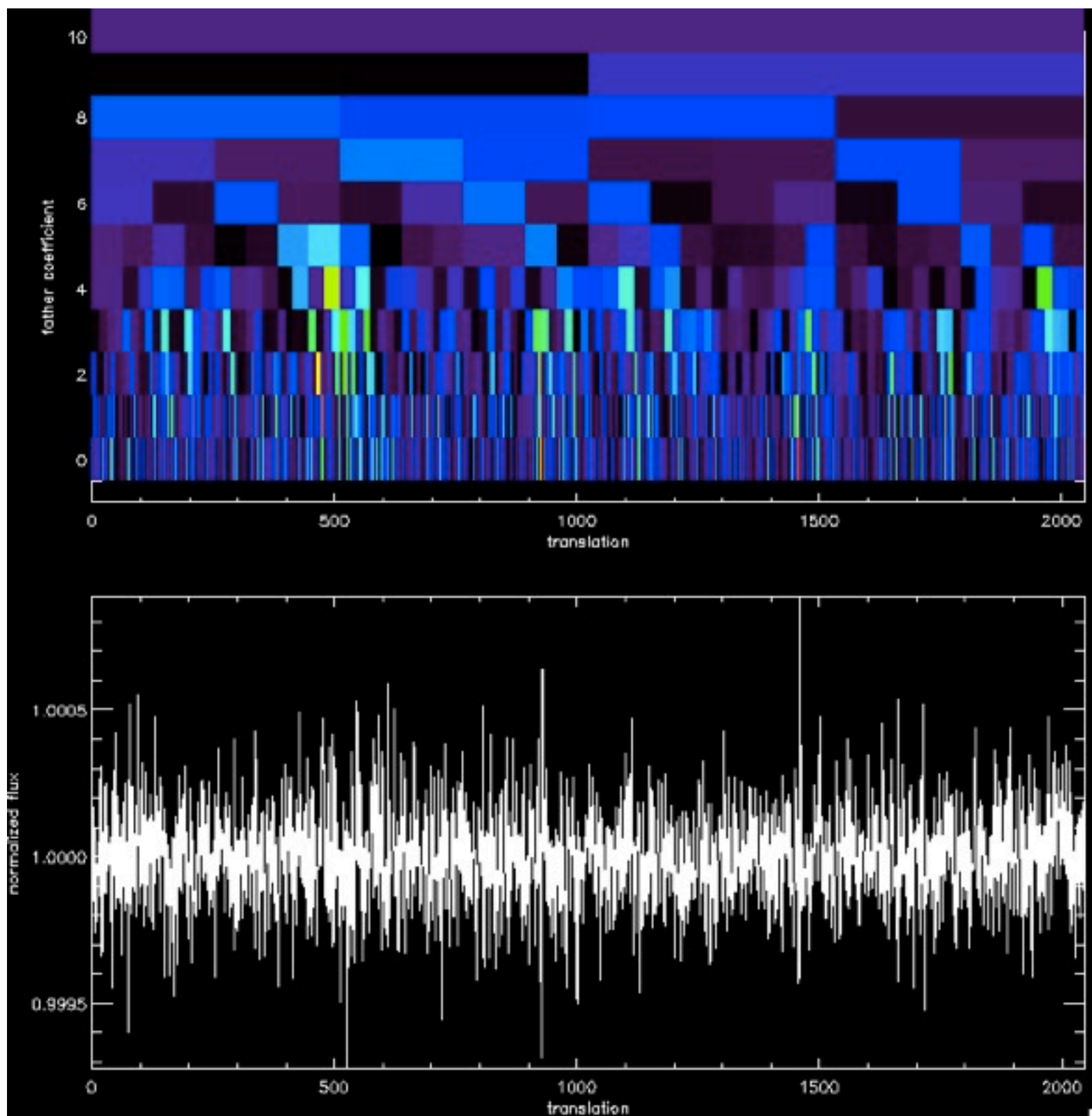
Wavelet



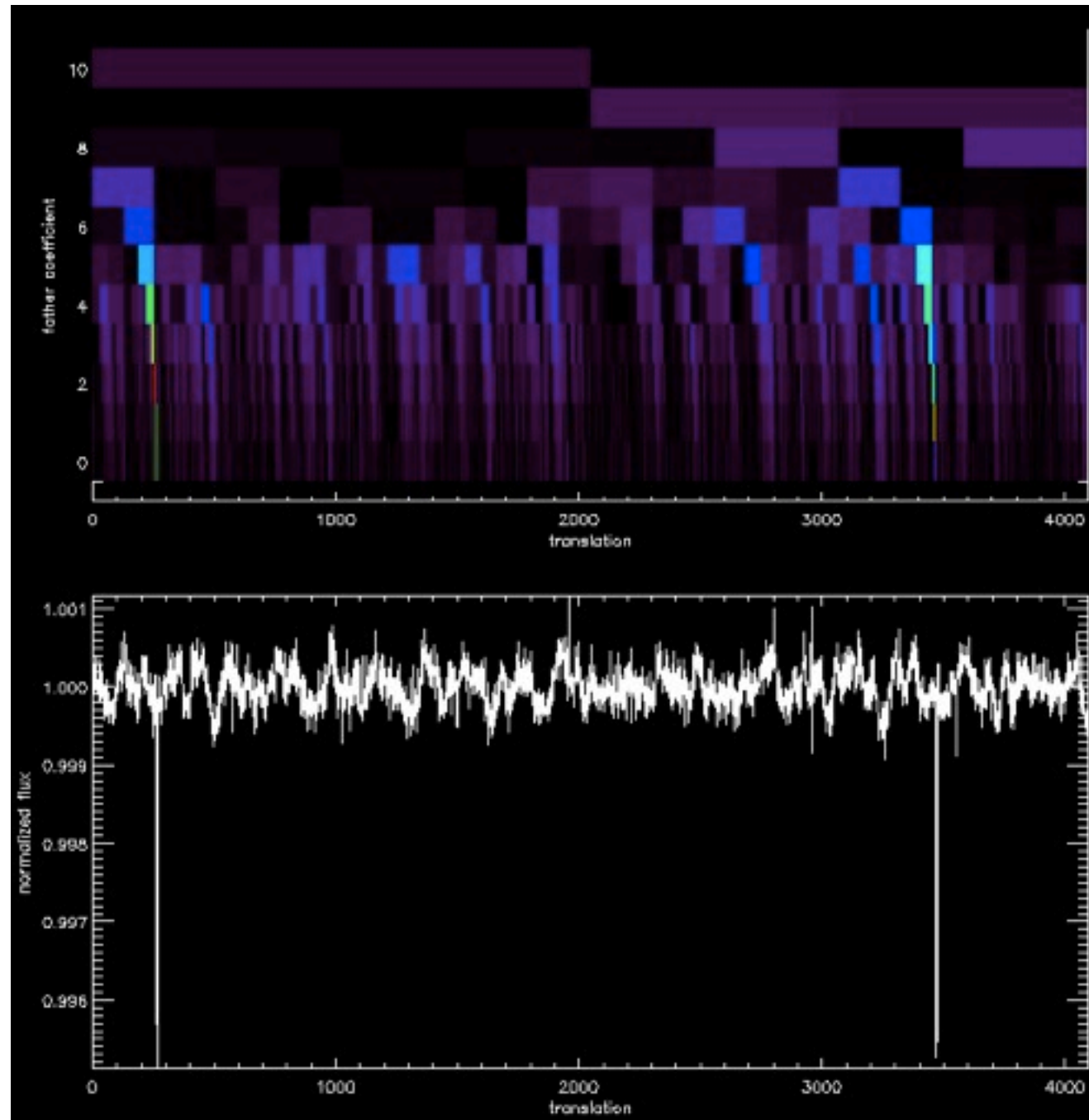
Medium filtered wavelet



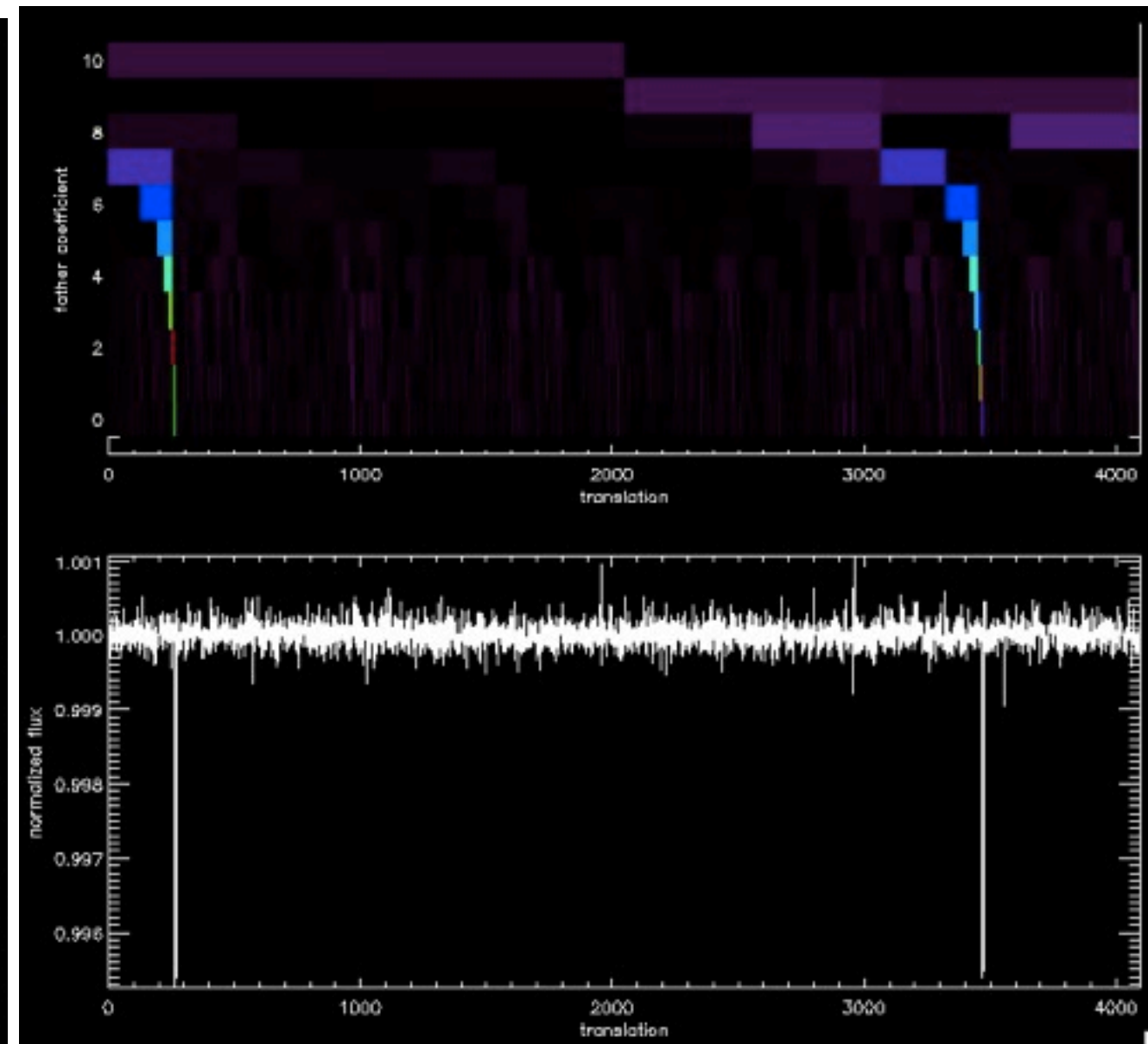
Medium filtered wavelet OOT



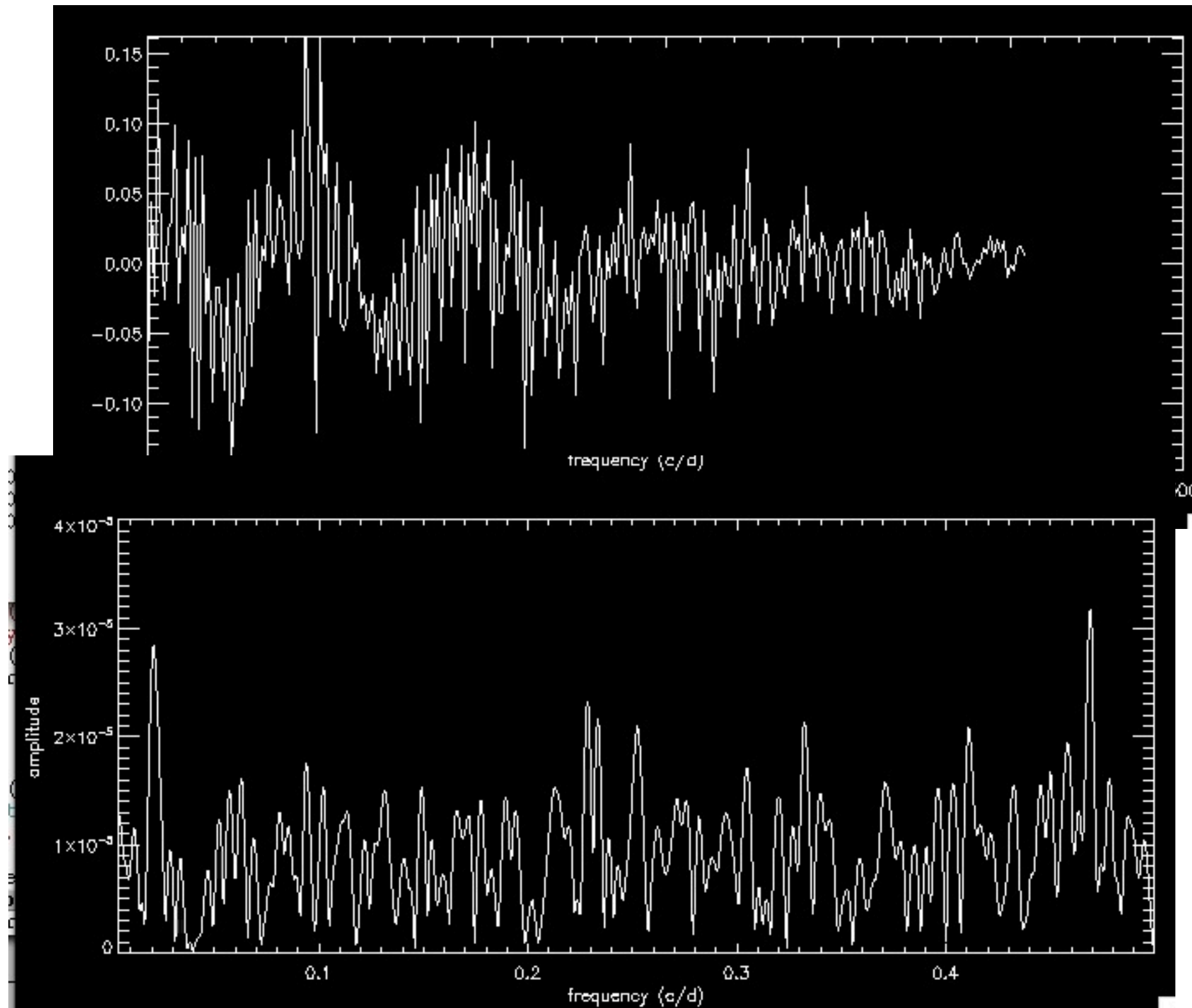
PDC



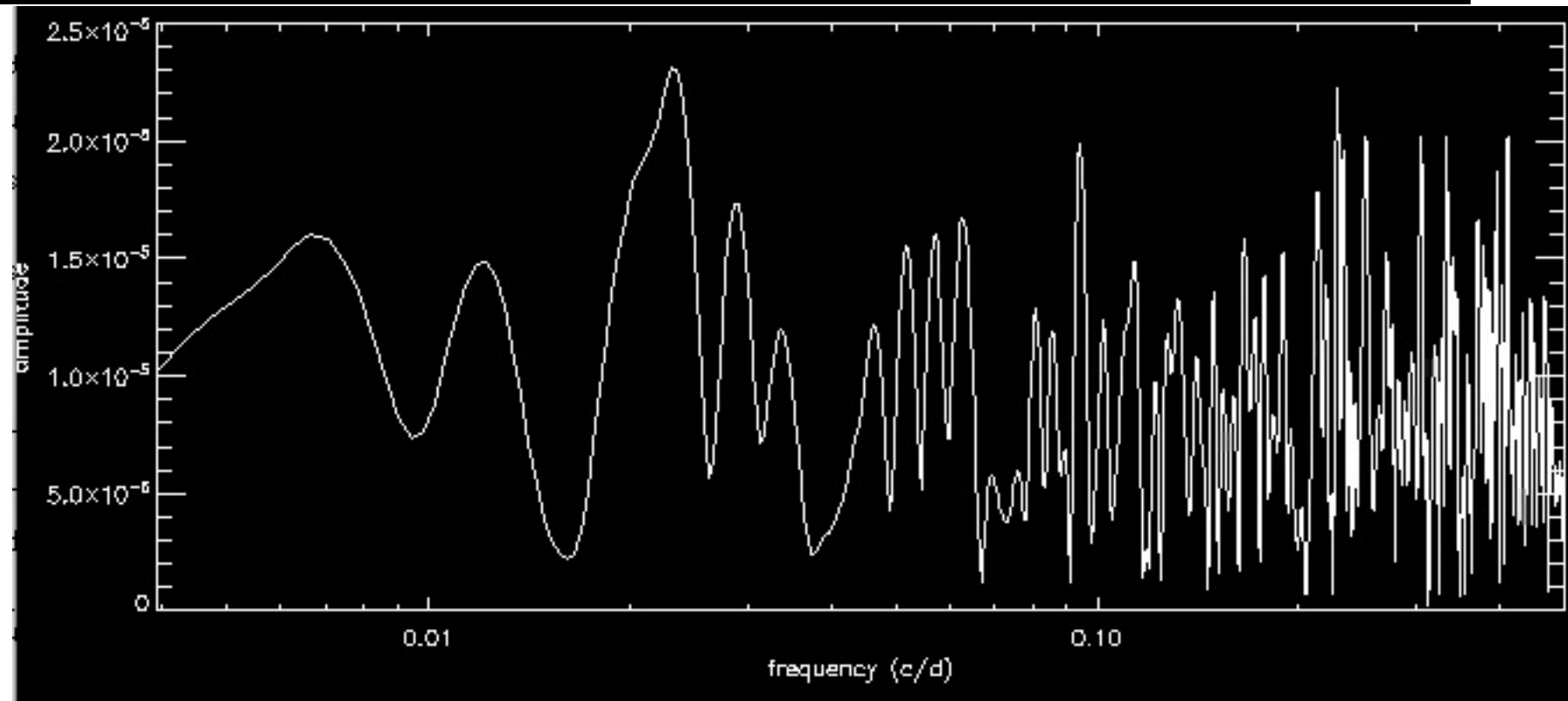
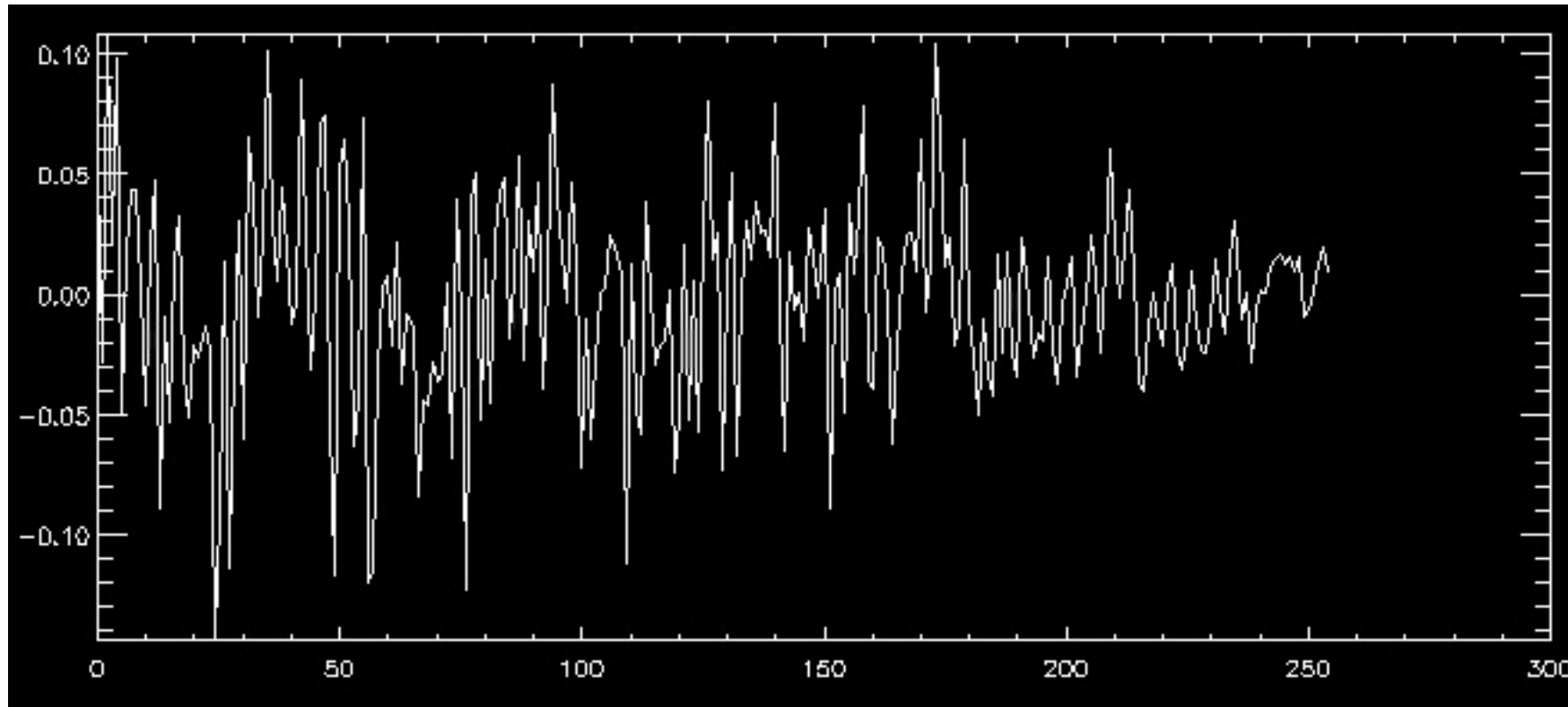
Medium PDC



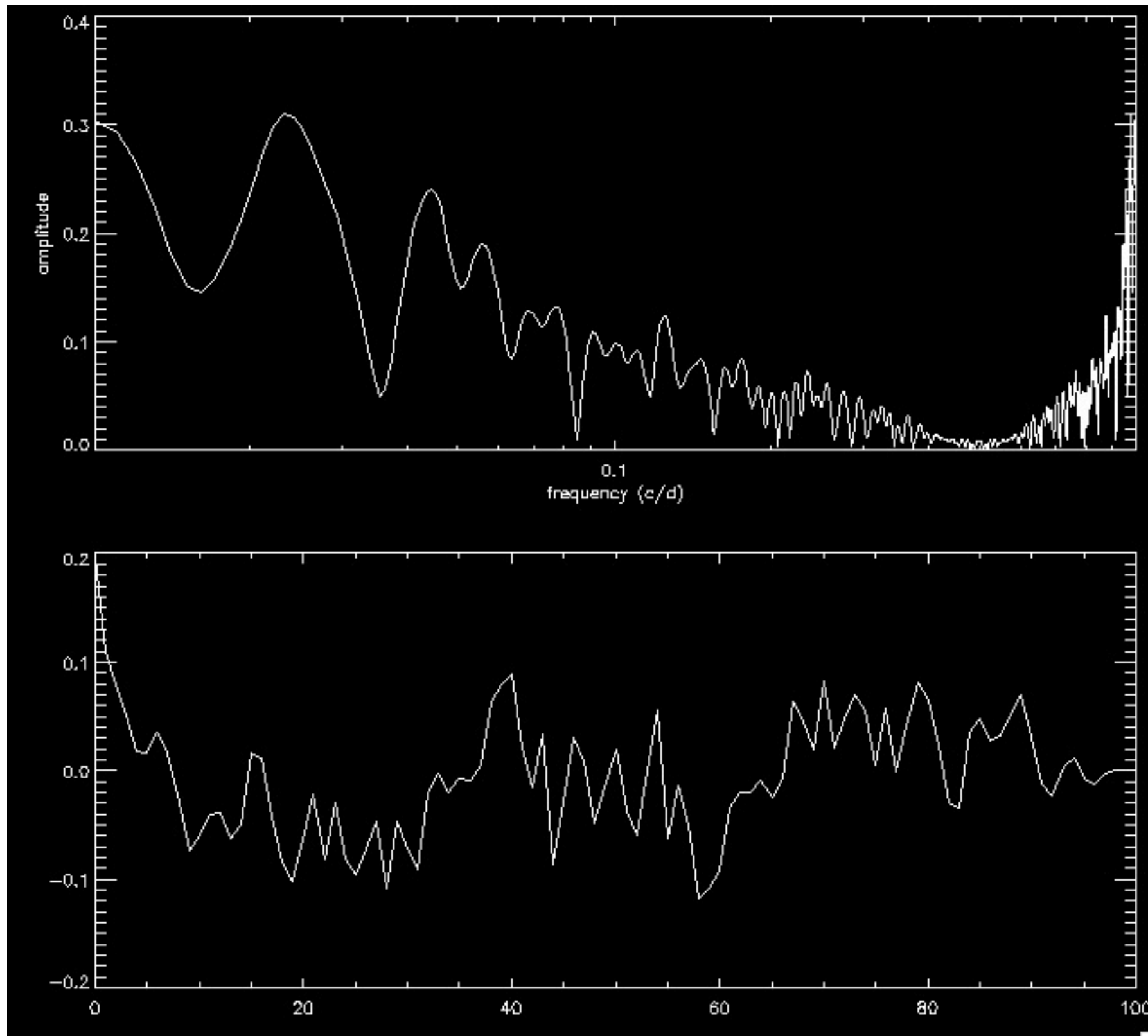
OOT Medium SAP



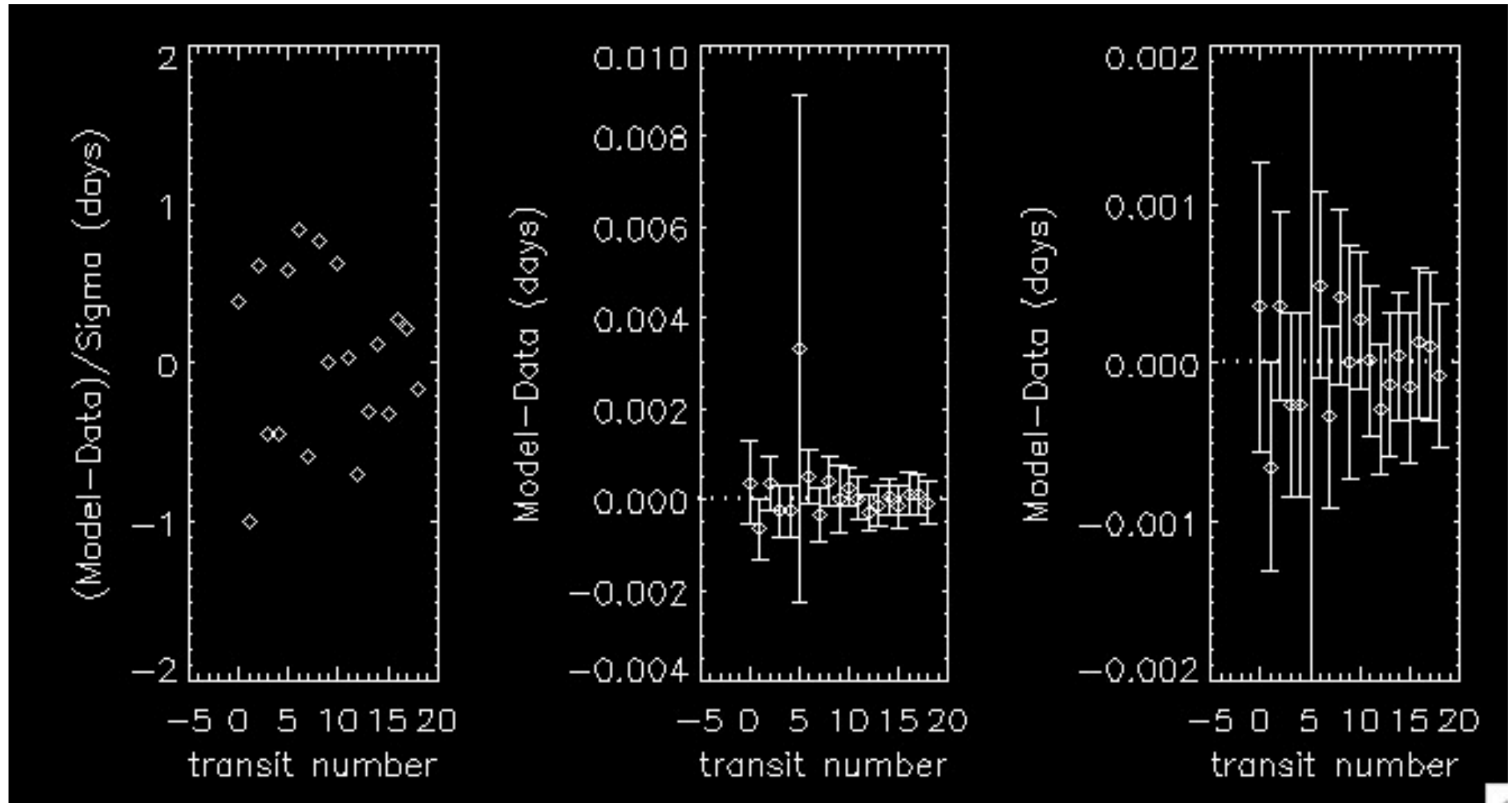
OOT Medium PDC



1/f noise



Residuals from transit timing dynamical model are too small



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Dynamical model only has 7 free parameters
KS probability of consistent with Gaussian is 1.4%
Error bars too large by factor of ~ 2

