



NTNU
Norwegian University of
Science and Technology

Week 44: Lecture 1
Conditional multivariate Gaussian distributions

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Information

- Minutes from reference group meeting 2 available under “course information”.
- We aim to conduct a physical exam with letter grades, but faculty/NTNU will assess the infection situation in the next two weeks.
- The backup plan is a digital home exam with pass/fail.
- Physical guidance on October 27 and November 3 in R2, and November 2 in S21/Smia.
- Looking into possibility for guidance also on November 5 or 6.
- Online intro course to R available here:
<https://digit.ntnu.no/courses/course-v1:NTNU+IMF001+2020/course/>

Section 2.3 (Note)

Example 1

$$\mathbf{X} \sim \mathcal{N}_2 \left(\begin{bmatrix} 1 \\ 2 \end{bmatrix}, \begin{bmatrix} 1 & 0.5 \\ 0.5 & 2 \end{bmatrix} \right).$$

- a) Determine the distribution of X_2 .
- b) Determine the distribution of $\bar{X} = 0.5(X_1 + X_2)$.

Theorem (Theorem 1)

Assume $\mathbf{X} \sim \mathcal{N}_n(\boldsymbol{\mu}, \Sigma)$ and \mathbf{L} is the Cholesky factor of Σ (i.e., $\Sigma = \mathbf{L}\mathbf{L}^T$). Then

- 1) $\mathbf{X} \sim \mathcal{N}_n(\boldsymbol{\mu}, \Sigma)$ implies $\mathbf{Z} = \mathbf{L}^{-1}(\mathbf{X} - \boldsymbol{\mu}) \sim \mathcal{N}_n(\mathbf{0}, \mathbf{I})$.
- 2) $\mathbf{Z} \sim \mathcal{N}_n(\mathbf{0}, \mathbf{I})$ implies $\mathbf{X} = \mathbf{L}\mathbf{Z} + \boldsymbol{\mu} \sim \mathcal{N}_n(\boldsymbol{\mu}, \Sigma)$.

Section 2.4 (Note)

Theorem (Theorem 2)

If

$$\mathbf{X} = (\mathbf{X}_A, \mathbf{X}_B) \sim \mathcal{N}_{n_A+n_B} \left(\begin{bmatrix} \boldsymbol{\mu}_A \\ \boldsymbol{\mu}_B \end{bmatrix}, \begin{bmatrix} \Sigma_{AA} & \Sigma_{AB} \\ \Sigma_{BA} & \Sigma_{BB} \end{bmatrix} \right),$$

where \mathbf{X}_A is n_A -dimensional and \mathbf{X}_B is n_B -dimensional, then

$$\mathbf{X}_A | \mathbf{X}_B = \mathbf{x}_B \sim \mathcal{N}_{n_A}(\boldsymbol{\mu}_C, \Sigma_C),$$

where

$$\boldsymbol{\mu}_C = \boldsymbol{\mu}_A + \Sigma_{AB} \Sigma_{BB}^{-1} (\mathbf{x}_B - \boldsymbol{\mu}_B)$$

$$\Sigma_C = \Sigma_{AA} - \Sigma_{AB} \Sigma_{BB}^{-1} \Sigma_{BA}.$$

Example 2

Assume $-1 < \rho < 1$ and $\sigma^2 > 0$, and let

$$(X_1, X_2, X_3) \sim \mathcal{N}_3 \left(\begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}, \sigma^2 \begin{bmatrix} 1 & \rho & \rho^2 \\ \rho & 1 & \rho \\ \rho^2 & \rho & 1 \end{bmatrix} \right).$$

Determine the distribution of $X_1|X_3 = x_3$.

Example 3

Assume $-1 < \rho < 1$ and $\sigma^2 > 0$, and let

$$(X_1, X_2, X_3) \sim \mathcal{N}_3 \left(\begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}, \sigma^2 \begin{bmatrix} 1 & \rho & \rho^2 \\ \rho & 1 & \rho \\ \rho^2 & \rho & 1 \end{bmatrix} \right).$$

Determine the distribution of $X_1 | X_2 = x_2, X_3 = x_3$.

Section 2.5 (Note)

Simulation from $\mathcal{N}_n(\boldsymbol{\mu}, \boldsymbol{\Sigma})$

Input:

n : dimension

$\boldsymbol{\mu}$: mean vector

$\boldsymbol{\Sigma}$: covariance matrix

Algorithm:

1. calculate Choleksy factorization $\boldsymbol{\Sigma} = \mathbf{L}\mathbf{L}^T$.
2. for $i = 1 \dots n$
3. draw $z_i \sim \mathcal{N}(0, 1)$
4. end
5. set $\mathbf{x} = \mathbf{L}\mathbf{z} + \boldsymbol{\mu}$

Output: \mathbf{x} is a simulation from $\mathcal{N}_n(\boldsymbol{\mu}, \boldsymbol{\Sigma})$.

Section 3 (Note)

Definition (Def. 1)

The stochastic process $\{B(t) : t \geq 0\}$ with state space \mathbb{R} is called **Brownian motion** with **variance parameter** $\sigma^2 > 0$ if

- 1) $B(s+t) - B(s) \sim \mathcal{N}(0, t\sigma^2)$ for $s \geq 0$ and $t > 0$.
- 2) for $0 \leq t_1 < t_2 \leq t_3 < t_4$,

$$B(t_2) - B(t_1) \quad \text{and} \quad B(t_4) - B(t_3)$$

are independent.

- 3) $B(0) = 0$ (and the realizations are continuous).

Example 4

We consider simulations from Brownian motions with

1. $\sigma^2 = 1$ and $t \in [0, 1]$
2. $\sigma^2 = 1$ and $t \in [0, 10]$
3. $\sigma^2 = 1/10$ and $t \in [0, 100]$
4. $\sigma^2 = 1/100$ and $t \in [0, 1000]$

Example 5

Let $\{B(t) : t \geq 0\}$ be Brownian motion with variance parameter $\sigma^2 > 0$. Derive an expression for the function $C(t, s) = \text{Cov}[B(t), B(s)]$.