Linear Dynamical Systems homework

Problem 1: simulation of an LDS

(a) Use the parameters in this file to sample N=10,000 states and observations from an LDS. Save the sampled values to use them on the next problem.

(b) Make a scatter plot with a trace with the first versus the second dimensions of the sampled states, and another trace with the first versus the second dimensions of the sampled observations.

The parameters in the previous file were used to generate the corresponding figure in the lectures notes. Hence your figure should be similar to the one on these notes.

Problem 2: inference in an LDS

(a) Filter and smooth the simulated observations from the previous problem with the model parameters used to generate the observations. The following Python module provides incomplete functions to perform Kalman filtering and smoothing. You may want to complete these functions to solve this problem.

(b) Generate a first scatter plot as in the previous problem, showing the state, observations, filtered and smoothed positions.

Generate a second scatter plot displaying the state, filtered and smoothed velocities as a function of sample number. This plot should contain six traces: `state_vel_x`, `filtered_vel_x`, `smoothed_vel_x`, `state_vel_y`, `filtered_vel_y` and `smoothed_vel_y`.

Generate a third scatter plot similar to the previous one, but for accelerations.