
Kalman Filter Theory and Applications Equation Drilldown

https://github.com/musicarroll/kalman_course

Michael L. Carroll

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Part I

The Five Basic Kalman Equations Topics

Part I

The Five Basic Kalman Equations

Topics

- Understanding the Equations: Heuristic Introduction

Part I

The Five Basic Kalman Equations

Topics

- Understanding the Equations: Heuristic Introduction
- **Equation Drilldown: Taking the Equations Apart**

Part I

The Five Basic Kalman Equations

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- Understanding the Equations: Heuristic Introduction
- **Equation Drilldown: Taking the Equations Apart**
- State Space Concepts

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Equation Drilldown: Taking the Equations Apart

Topics

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- Mathematical Formulation of the Problem

Equation Drilldown: Taking the Equations Apart

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- Drilldown on State Dynamics and Covariance Extrapolation Equations

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- **Examples: Damped Harmonic Oscillator**

Equation Drilldown: Taking the Equations Apart

Topics

- Mathematical Formulation of the Problem
- Drilldown on State Dynamics and Covariance Extrapolation Equations
- The Five Kalman Filter Equations
- **Examples: Damped Harmonic Oscillator**
- Exercises

Equation Drilldown: Taking the Equations Apart

Topics

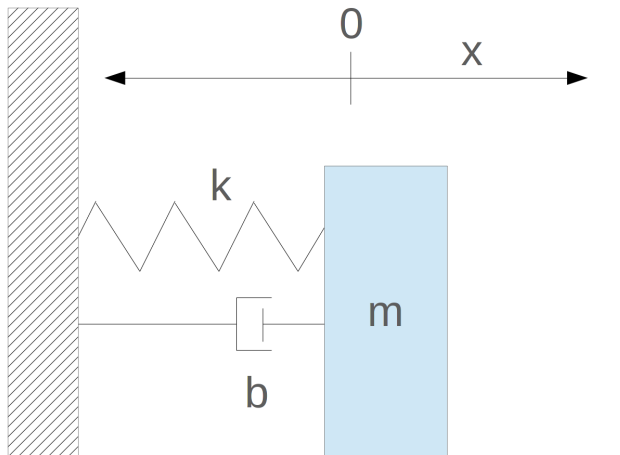
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 - **Examples: Damped Harmonic Oscillator**
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Damped Harmonic Oscillator

Spring, Mass, Damper System

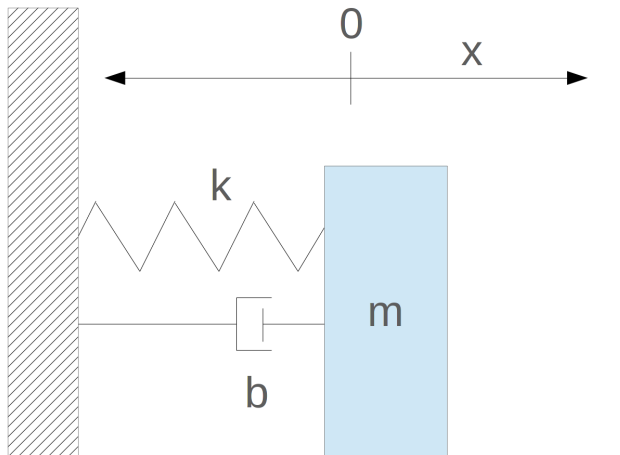
Damped Harmonic Oscillator

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System Dynamics

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$$\begin{bmatrix} x_1(j) \\ x_2(j) \end{bmatrix} = \exp \left(\begin{bmatrix} 0 & 1 \\ -b/m & -k/m \end{bmatrix} \Delta t \right) \begin{bmatrix} x_1(j-1) \\ x_2(j-1) \end{bmatrix} + \begin{bmatrix} w_1(j) \\ w_2(j) \end{bmatrix}$$

- Thus, $\Phi(\Delta t) = \exp \left(\begin{bmatrix} 0 & 1 \\ -b/m & -k/m \end{bmatrix} \Delta t \right)$.

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- Here $\Delta t = t_j - t_{j-1}$, m is the mass, k is the spring constant, and b is the damping constant; we are using t for the time step index, to avoid clash with spring constant

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Damped Harmonic Oscillator

Measurement Model

Damped Harmonic Oscillator

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$$z(j) = \begin{bmatrix} 1 & 0 \end{bmatrix} \begin{bmatrix} x_1(j) \\ x_2(j) \end{bmatrix} + v(j)$$

where the measurement noise $v(j)$ has variance σ^2

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- Moreover, like Φ , which is derived from a continuous model, Q is also dependent on Δt and q , the continuous process noise variance:

$$Q = q \begin{bmatrix} \frac{(\Delta t)^3}{3} & \frac{(\Delta t)^2}{2} \\ \frac{(\Delta t)^2}{2} & \Delta t \end{bmatrix}$$

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Damped Harmonic Oscillator Estimator

MATLAB/Python Run

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- $\Delta t = 0.1$ sec, 50 samples,
50% process noise assumption factor

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- Light spring: $k = 1$ N/m

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- $m = 1$ kg
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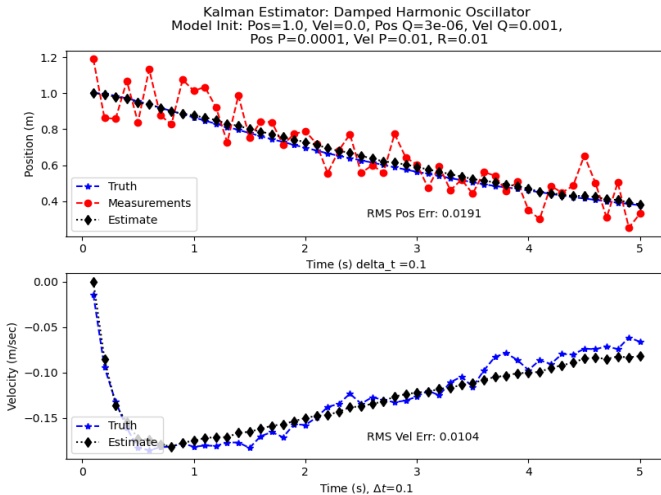
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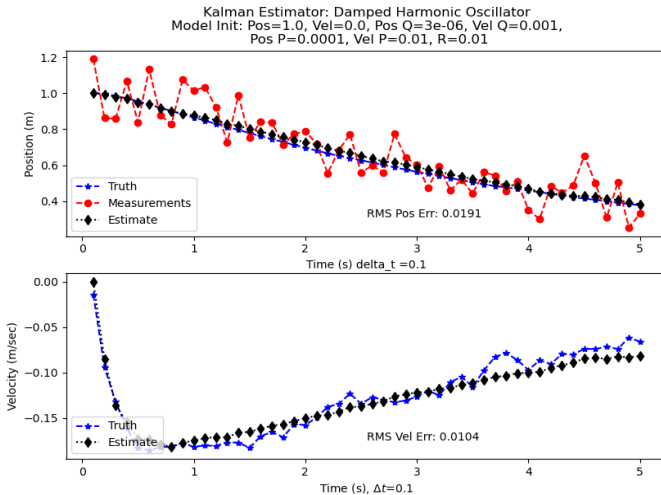
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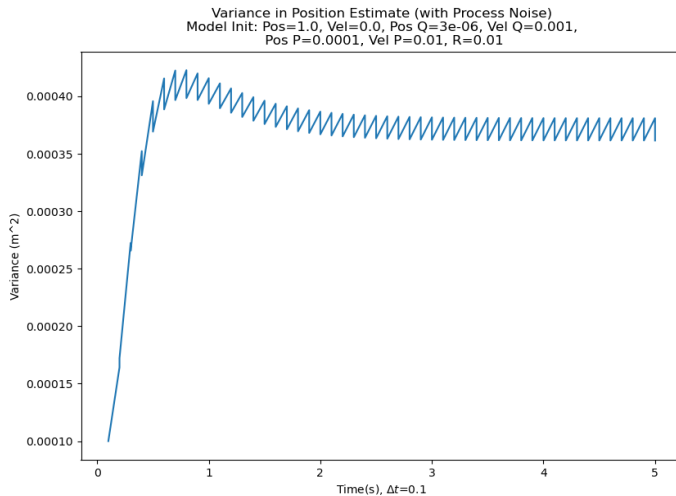


Damped Harmonic Oscillator Estimator

Sawtooth Plots

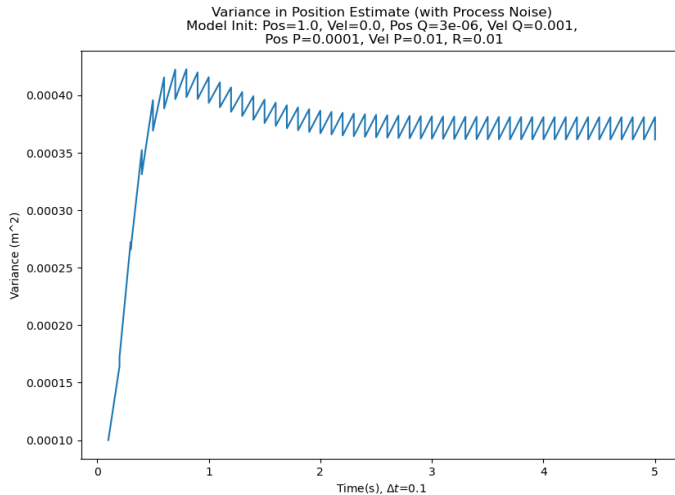
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Damped Harmonic Oscillator Estimator

MATLAB/Python Run

- $\Delta t = 1$ sec, 50 samples,
50% process noise assumption factor
 - $m = 1$ kg
 - Light spring: $k = 1$ N/m
 - Medium damping: $b = 5$ Ns/m
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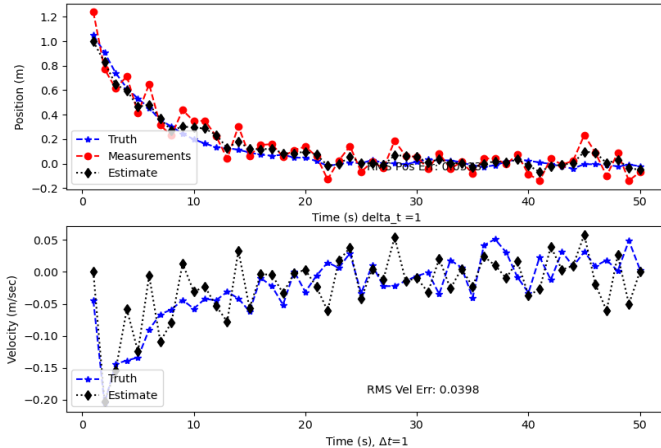
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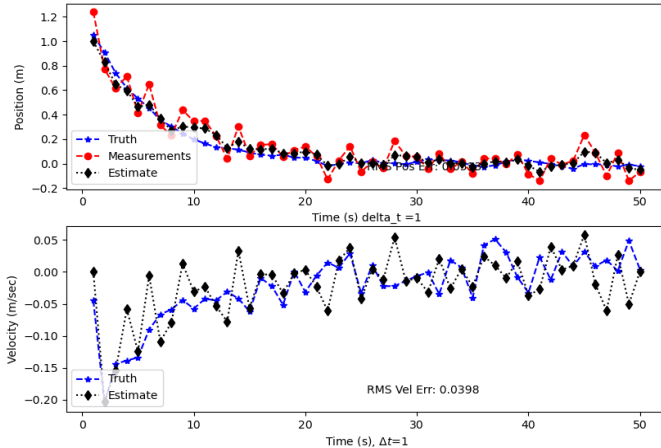
Kalman Estimator: Damped Harmonic Oscillator
Model Init: Pos=1.0, Vel=0.0, Pos Q=0.003333, Vel Q=0.01,
Pos P=0.0001, Vel P=0.01, R=0.01



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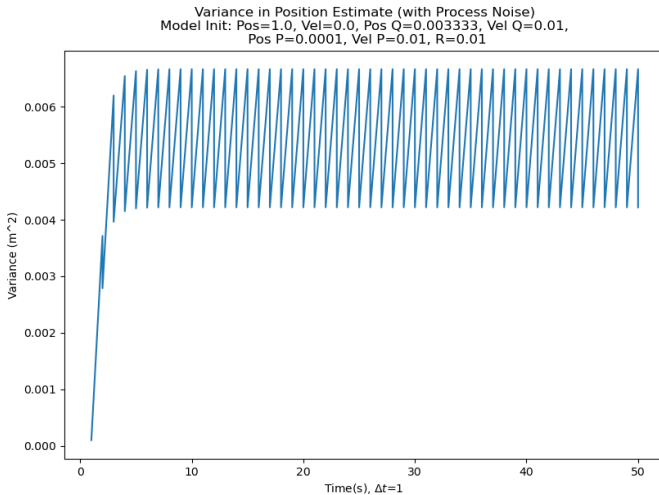


Damped Harmonic Oscillator Estimator

Sawtooth Plots

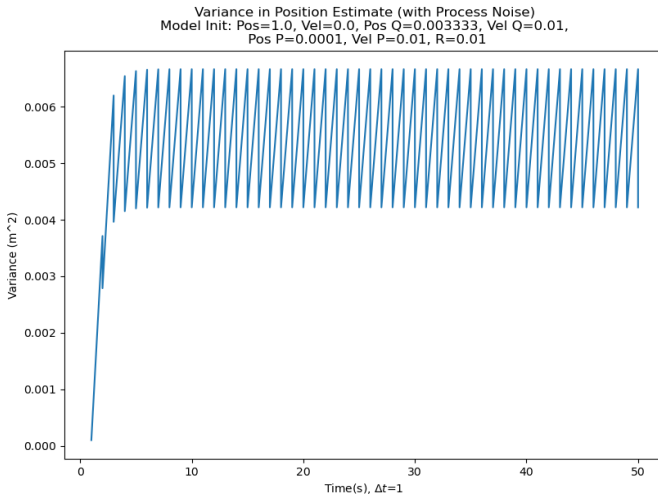
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