Kalman filter

intuition: scalar case

$$\text{KG} = \text{Kalman Gain} = \frac{E_{est}}{E_{est} + E_{meas}} \qquad 0 \le KG \le 1$$

$$est_t = est_{t-1} + KG[mea - est_{t-1}]$$

E_{est} = error in the estimate. If the KG is large (close to 1), that means E_{meas} (R) is small (accurate measurement, unstable estimate, large Q) therefore we want to move est closer towards mea. On the other hand, if KG is small that means E_{meas} (R) is large (inaccurate measurement, stable estimates, small Q) we don't want to take much of the difference, $mea - est_{t-1}$.

$$E_{est_t} = \frac{E_{mea} E_{est_{t-1}}}{E_{mea} + E_{est_{t-1}}} \Rightarrow E_{est_t} = [1 - KG] E_{est_{t-1}}$$

In the above error in the estimate update, we observe that if KG is large ($1-KG$ is small) then E_{est} converge faster. On the other hand, if KG is small, it takes longer time for E_{est} to converge (larger $(1 - KG)$).
recap:

- High SNR=Q/R (Signal to Noise Ratio) in the model, gives a fast filter that is quick to adapt to changes/maneuvers, but with larger uncertainty (small bias, large variance).
- Low SNR in the model, gives a slow filter that is slow to adapt to changes /maneuvers, but with small uncertainty (large bias, small variance).

Note: bias = measured − estimate.

Kalman filter steps:

1. calculate Kalman Gain (KG)
2. calculate current estimate
3. update estimate error

model state space
The Kalman filter assumes that we have a state vector $\mathbf{x} \in \mathbb{R}^n$ which evolves in the following way:

$$x_k = A_{k-1} x_{k-1} + B_{k-1} u_{k-1} + q_{k-1}$$

where $A_{k-1} \in \mathbb{R}^{n \times n}$ is the state transition matrix, $q_{k-1} \in \mathbb{R}^n$ is process noise. $B_{k-1} \in \mathbb{R}^{n \times r}$ is a matrix that multiplies the control vector $u \in \mathbb{R}^{r \times 1}$. In addition we need to have some measurements $y_k \in \mathbb{R}^m$, modeled as:

$$y_k = H x_k + r_k$$

Here $H \in \mathbb{R}^{m\times n}$ denotes the measure matrix, and it being constant here means we measure the same linear combinations of the state-vector components at each time. The vector r_k is another noise, which models measurement errors.

In order to use the Kalman filter, we need to suppose that the initial distribution x_0 from which it starts is Gaussian, and that the noises are Gaussian zero-mean:

$$x_0 \sim \mathcal{N}(\mu_0, \Sigma_0)$$
$$q_k \sim \mathcal{N}(0, \Sigma_q)$$
$$r_k \sim \mathcal{N}(0, \Sigma_r)$$

we also assume that the noises are not temporally correlated, this means $E[q_k q_j^T] = \Sigma_q \delta_{kj}$ and $E[r_k r_j^T] = \Sigma_r \delta_{kj}$, and that the noises and the state are mutually statistically independent, $E[x_k r_j^T] = 0 \quad \forall k, j$ and $E[x_k q_j^T] = 0 \quad \forall j > k$ (the state is correlated with previous noises, $j < k$ since the noises appears in the state evolution equation). Finally the two noises are required to be mutually independent: $E]r_k q_j^T] = 0 \quad \forall k, j$

propagation of state error

Estimating the state x_k is optimally performed by iterating between uncertainty propagation and measurement updates. The mean and covariance after propagation from step $k-1$ to step k are denoted by $(x_{k|k-1}, \Sigma_{k|k-1})$. The mean and covariance after a measurement update at step k are denoted by $(x_{k|k}, \Sigma_{k|k})$. Given the discrete linear, time-varying (LTV) model of x, we define the state prediction as:

$$\hat{x}_{k|k-1} = A_{k-1}\hat{x}_{k-1,k-1} + B_{k-1}u_{k-1}$$

which is equivalent to the mean,

$$E[x_k|x_{k-1}] = A_{k-1}\bar{x}_{k-1} + B_{k-1}u_{k-1} + E[q_k] = A_{k-1}\bar{x}_{k-1} + B_{k-1}u_{k-1}$$

note that the control matrix and vector are, for our purposes considered as constants since they only vary over time but are deterministic at each timestep. This means that u_k is not drawn from a probability distribution, and $E[u_k] = u_k \qquad \forall k$. We have the covariance of this state estimate,

$$\Sigma_{k|k-1} = E[(x_{k|k-1} - \hat{x}_{k|k-1})(x_{k|k-1} - \hat{x}_{k|k-1})^T]$$

$$= E[(A_{k-1}(x_{k-1,k-1} - \hat{x}_{k-1,k-1}) + q_{k-1})(A_{k-1}(x_{k-1,k-1} - \hat{x}_{k-1,k-1}) + q_{k-1})^T]$$
$$= E[A_{k-1}(x_{k-1,k-1}-\hat{x}_{k-1,k-1})(x_{k-1,k-1}-\hat{x}_{k-1,k-1})A_{k-1}^T + A_{k-1}(x_{k-1,k-1}-\hat{x}_{k-1,k-1})q_{k-1}$$
$$+q_{k-1}(x_{k-1,k-1} - \hat{x}_{k-1,k-1})^T A_{k-1}^T + q_{k-1}q_{k-1}^T]$$

$x_{k-1} - \bar{x}_{k-1}$ and q_{k-1} i.e. state error and state are uncorrelated implies

$$E[(x_{k-1,k-1} - \hat{x}_{k-1,k-1})q_{k-1}^T] = E(x_{k-1,k-1} - \hat{x}_{k-1,k-1})E(q_{k-1}^T) = 0$$

also

$$E[q_{k-1}(x_{k-1,k-1} - \hat{x}_{k-1,k-1})^T] = 0$$

two of the summands in the equation for $\Sigma_{k|k-1}$ vanish. The recursive covariance equation reduces to

$$\Sigma_{k|k-1} = A_{k-1}\Sigma_{k-1,k-1}A_{k-1}^T + \Sigma_q$$

which is actually how the covariance of a variable resulting from the affine transformation (from the model's linearity assumption) of x, i.e. $y = Ax + b$, will propagate over time.

finding the optimum x

we are given measurements y, whose error is Σ_r. How can we get the best estimate $\hat{x}$ which minimizes the errors weighted by the accuracy (inverse of Σ_r, Σ_r^{-1})?. But we are also given a priori estimate of the state, $\hat{x}_{k|k-1}$ with covariance $\Sigma_{k|k-1}$. This can be achieved by minimizing the quadratic cost function

$$J(\hat{x}) = \frac{1}{2}\Big((y_k - H\hat{x}_k)^T\Sigma_r^{-1}(y_k - H\hat{x}_k) + (\hat{x}_{k|k-1} - \hat{x}_k)^T\Sigma_{k|k-1}^{-1}(\hat{x}_{k|k-1} - \hat{x}_k)\Big)$$

The idea is to use the old information together with this newly observed information to arrive at the best estimate of x. Intuitively a small standard deviation means bigger error, which means it will more importance in the cost function.

$$\frac{\partial J}{\partial \hat{x}} = -H^T\Sigma_r^{-1}(y_k - H\hat{x}_k) - \Sigma_{k|k-1}^{-1}(\hat{x}_{k|k-1} - \hat{x}_k) = 0$$

$$-H^T\Sigma_r^{-1}y_k + H^T\Sigma_r^{-1}H\hat{x}_k - \Sigma_{k|k-1}^{-1}\hat{x}_{k|k-1} + \Sigma_{k|k-1}^{-1}\hat{x}_k = 0$$

$$(H^T\Sigma_r^{-1}H + \Sigma_{k|k-1}^{-1})\hat{x}_k = H^T\Sigma_r^{-1}y_k + \Sigma_{k|k-1}^{-1}\hat{x}_{k|k-1}$$

$$\hat{x}_k = (H^T\Sigma_r^{-1}H + \Sigma_{k|k-1}^{-1})^{-1}(H^T\Sigma_r^{-1}y_k + \Sigma_{k|k-1}^{-1}\hat{x}_{k|k-1})$$

Woodbury matrix identity:

$$(A + BCD)^{-1} = A^{-1} - A^{-1}B(C^{-1} + DA^{-1}B)^{-1}DA^{-1}$$

utilizing this identity,

$$(H^T\Sigma_r^{-1}H + \Sigma_{k|k-1}^{-1})^{-1} = \Sigma_{k|k-1} - \Sigma_{k|k-1}H^T(\Sigma_r + H\Sigma_{k|k-1}H^T)^{-1}H\Sigma_{k|k-1}$$

$$\begin{aligned}\hat{x}_k =& \Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k + \hat{x}_{k|k-1} - \Sigma_{k|k-1}H^T(\Sigma_r + H\Sigma_{k|k-1}H^T)^{-1}H\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k \\ &- \Sigma_{k|k-1}H^T(\Sigma_r + H\Sigma_{k|k-1}H^T)^{-1}H\hat{x}_{k|k-1} \\ =& \hat{x}_{k|k-1} + (\mathbb{I} - \Sigma_{k|k-1}H^T(\Sigma_r + H\Sigma_{k|k-1}H^T)^{-1}H)\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k \\ &- \Sigma_{k|k-1}H^T(\Sigma_r + H\Sigma_{k|k-1}H^T)^{-1}H\hat{x}_{k|k-1}\end{aligned}$$

define K_k,

$$K_k = \Sigma_{k|k-1}H^T(\Sigma_r + H\Sigma_{k|k-1}H^T)^{-1}$$

$$\hat{x}_k = \hat{x}_{k|k-1} + (I - KH)\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k - KH\hat{x}_{k|k-1} \tag{1}$$

analyse the second term,

$$(I - KH)\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k = \Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k - KH\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k \tag{2}$$

from the definition of K,

$$K(\Sigma_r + H\Sigma_{k|k-1}H^T) = \Sigma_{k|k-1}H^T \tag{3}$$

substituting this to (2),

$$\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k - KH\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k = K(\Sigma_r + H\Sigma_{k|k-1}H^T)\Sigma_r^{-1}y_k - KH\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k$$

$$= K\Sigma_r\Sigma_r^{-1}y_k + KH\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k - KH\Sigma_{k|k-1}H^T\Sigma_r^{-1}y_k = Ky_k$$

Hence, substituting back the second term to (1),

$$\begin{aligned}\hat{x}_{k|k} &= \hat{x}_{k|k-1} + K_k y_k - K_k H\hat{x}_{k|k-1} \\ &= \hat{x}_{k|k-1} + K_k(y_k - H\hat{x}_{k|k-1})\end{aligned}$$

where $K_k \in \mathbb{R}^{n\times m}$ denotes the Kalman Gain.

covariance update
posteriori error,

$$\begin{aligned}x_{k|k-1} - \hat{x}_{k|k} &= x_{k|k-1} - (\hat{x}_{k|k-1} + Ky_k - KH\hat{x}_{k|k-1}) \\ &= x_{k|k-1} - (\hat{x}_{k|k-1} + K(Hx_{k|k-1} + r_k) - KH\hat{x}_{k|k-1}) \\ &= x_{k|k-1} - \hat{x}_{k|k-1} - KHx_{k|k-1} - Kr_k + KH\hat{x}_{k|k-1} \\ &= (\mathbb{I} - KH)(x_{k|k-1} - \hat{x}_{k|k-1}) - Kr_k\end{aligned}$$

$$\Sigma_{k|k} = E[((\mathbb{I}-KH)(x_{k|k-1}-\hat{x}_{k|k-1})-Kr_k)((\mathbb{I}-KH)(x_{k|k-1}-\hat{x}_{k|k-1})-Kr_k)^T]$$

$$= E[(\mathbb{I}-KH)(x_{k|k-1}-\hat{x}_{k|k-1})(x_{k|k-1}-\hat{x}_{k|k-1})^T(\mathbb{I}-KH)^T - (\mathbb{I}-KH)(x_{k|k-1}-\hat{x}_{k|k-1})r_k^TK^T$$

$$-Kr_k(x_{k|k-1} - \hat{x}_{k|k-1})^T(1 - KH)^T + Kr_kr_k^TK^T]$$

$$= (\mathbb{I} - KH)\Sigma_{k|k-1}(I - KH)^T + K\Sigma_rK^T$$

The above covariance update form is called the **Joseph form** (a more stable update form).

$$\Sigma_{k|k} = \Sigma_{k|k-1} - \Sigma_{k|k-1}H^TK^T - KH\Sigma_{k|k-1} + KH\Sigma_{k|k-1}H^TK^T + K\Sigma_rK^T$$

substituting (3),

$$\begin{aligned}\Sigma_{k|k} = &\\ &\Sigma_{k|k-1} - K(\Sigma_r + H\Sigma_{k|k-1}H^T)K^T - KH\Sigma_{k|k-1} + KH\Sigma_{k|k-1}H^TK^T + K\Sigma_rK^T \\ =&\Sigma_{k|k-1} - K\Sigma_rK^T - KH\Sigma_{k|k-1}H^TK^T - KH\Sigma_{k|k-1} + KH\Sigma_{k|k-1}H^TK^T + K\Sigma_rK^T \\ =&\Sigma_{k|k-1} - KH\Sigma_{k|k-1} = (\mathbb{I} - KH)\Sigma_{k|k-1}\end{aligned}$$

kalman filter algorithm

$\hat{x}_{k\|k-1} = A_{k-1}\hat{x}_{k-1,k-1} + B_{k-1}u_{k-1}$	state prediction
$\Sigma_{k\|k-1} = A_{k-1}\Sigma_{k-1,k-1}A_{k-1}^T + \Sigma_q$	prediction covariance
$K_k = \Sigma_{k\|k-1}H^T(\Sigma_r + H\Sigma_{k\|k-1}H^T)^{-1}$	calculate Kalman Gain
$\hat{x}_{k\|k} = \hat{x}_{k\|k-1} + K_k(y_k - H\hat{x}_{k\|k-1})$	state correction/update
$\Sigma_{k\|k} = (\mathbb{I} - KH)\Sigma_{k\|k-1}$	update covariance matrix

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