State-space PTA

Kimpson[1], Melatos,O'Leary, , Evans, others, etc. ⋆ †
[1]*Royal Astronomical Society, Burlington House, Piccadilly, London W1J 0BQ, UK*

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ABSTRACT
This is an abstract

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1 INTRODUCTION

The detection of high frequency ($\sim$ 1Hz) gravitational waves (GWs) from coalescing BH binaries with ground-based detectors such as LIGO/Virgo (LIGO Scientific Collaboration et al. 2015; Acernese et al. 2015) is now a routine enterprise (e.g. Abbott et al. 2019, 2021). Gravitational radiation from sources which radiate in the mill-Hz regime are expected to be detectable from $\sim$ 2030 with the space-based Laser Interferometer Space Antenna, (Amaro-Seoane et al. 2017) especially given the early success by the pathfinder mission (Armano et al. 2019). Detecting GWs from systems which evolve over even longer timescales, $\mathcal{O}$(years), has necessitated the development of novel astrophysical methods, since it is practically impossible to engineer interferometric detectors with sufficiently long baselines. The foremost technique for the detection of GWs in this nano-Hz regime is a via timing an ensemble of milliseconds pulsars; a pulsar timing array (PTA) (Verbiest et al. 2021). The presence of a nano-Hz gravitational wave will influence the propagation of the pulsar radio beacon, leaving a characteristic impression on the pulsar timing signal. By measuring the modulation of the received pulsar signal in this way, one can effectively construct a detector with a baseline on the scale of parsecs.

Multiple PTA detectors have now been built over the last few decades, including the North American Nanohertz Observatory for Gravitational Waves (NANOGrav, Arzoumanian et al. 2020), the Parkes Pulsar Timing array (PPTA Kerr et al. 2020), and the European Pulsar Timing Array (EPTA, Ferdman et al. 2010). These previously disparate efforts have now been joined in international collaboration, along with a number of newer PTAs, under the umbrella of the International Pulsar Timing Array (IPTA Perera et al. 2019). The primary target of PTA observations is the gravitational radiation emitted from the inspiral of supermassive black hole binaries (SMBHBs) with masses $\sim$ ∞ɼ'$\mathcal{M}_\odot$. These GW signals from SMBHBs can be broadly classified into either deterministic or stochastic. For the former, sufficiently bright and near binaries may be resolvable with PTAs, allowing the very earliest stages of their evolution and coalescence to be investigated. For the latter, the incoherent superposition of multiple weaker SMBHBs sources leads to a stochastic background detectable at nano-Hz frequencies. Other potential sources for PTAs include cosmic strings (e.g. Sanidas et al. 2012) and cosmological phase transitions (e.g. Xue et al. 2021), but the deterministic and stochastic GW signals from SMBHBs remain the primary targets.

The detection of loud, resolved sources with a PTA typically involves a parametrised model for the pulsar timing residuals induced by the modulation of the pulsar signal by a GW. One can then search for evidence that this model describes the data via the usual Bayesian likelihood techniques, and try to estimate the parameters of the model (e.g. Babak et al. 2016). For detecting the stochastic background the approach is different; one measures the correlation in pulsar timing residuals between any two pair of pulsars. The presence of a GW induces a characteristic correlation function as a function of the angular separation between the pulsars; the Hellings-Downs curve (Hellings & Downs 1983). For both classes of source, detection of GW signals in the timing residuals of a PTA is a challenging enterprise, and currently neither a stochastic background nor an individually resolved source has yet been detected (Antoniadis et al. 2022; Hobbs & Dai 2017).

Motivated by the difficulties faced by the classic PTA analysis methods, in this work we present a novel approach to formulate PTA analysis and GW detection as a state-space problem. This approach enables the state-space evolution to be tracked optimally, and for a specific realisation of the pulsar process noise (i.e. the spin wandering of the pulsar) infer both the system parameters and the detectability of the GW signal. For this initial exploratory study we will focus exclusively on resolved, monochromatic GW sources.

This paper is organised as follows. [1]

2 STATE-SPACE MODEL

We want to formulate the PTA analysis as a state-space problem with a separation between the intrinsic pulsar state and the measurement

⋆ Contact e-mail: mn@ras.ac.uk
† Present address: Science magazine, AAAS Science International, 82-88 Hills Road, Cambridge CB2 1LQ, UK

[1] 1. Introduce PTAs generally. 2.Types of astrophysical source to be detected with PTAs. 3. Previous methods. 4. Challenges/problems of previous methods. 5. Our approach and its potential advantages.

state recorded by an observer. We will take our state to be the pulsar pulse frequency $f(t)$. We will now consider how the intrinsic pulse frequency evolves in time, completely separate from the influence of a GW, and then go on to derive the influence of a GW perturbation on the frequency recorded by an observer at Earth.

2.1 Evolution of the pulsar frequency

We will take as our model of the intrinsic pulsar frequency f a variation of the phenomenological model of (Vargas & Melatos 2023). Within this model, f evolves according to a combination of both deterministic torques (i.e. electromagnetic spin-down) and stochastic torques (i.e. 'spin wandering', achromatic variations in the pulse TOA intrinsic to the star). The deterministic torque is taken to arise from the pulsar magnetic dipole, with braking index $n = 3$ whilst the stochastic torque is a simple white noise process. Specifically, the frequency evolves according to a Ornstein-Uhlenbeck process (equivalently a Langevin equation) with a time-dependent drift parameter:

$$\frac{df}{dt} = -\gamma[f - f_{\rm EM}(t)] + \dot{f}_{\rm EM} + \xi(t) \tag{1}$$

where $f_{\rm EM}$ is the solution of the electromagnetic spindown equation, γ a proportionality constant, and $\xi(t)$ a white noise process that satisfies,

$$\langle \xi(t)\xi(t') \rangle = \sigma^2 \delta(t - t') \tag{2}$$

For PTA analysis, we are concerned with timescales on the order of years. Consequently, we can express the EM spindown straightforwardly as

$$f_{\rm EM}(t) = f_{\rm EM}(0) + \dot{f}_{\rm EM}(0)t \tag{3}$$

Completely, the frequency evolution is then given by the solution of the stochastic differential equation,

$$\frac{df}{dt} = -\gamma[f - f_{\rm EM}(0) - \dot{f}_{\rm EM}(0)t] + \dot{f}_{\rm EM}(0) + \xi(t) \tag{4}$$

As emphasised in Vargas & Melatos (2023), this model for the frequency evolution is a phenomenological model that aims to qualitatively reproduce the typical behaviour of observed pulsars, rather than being derived from a physical model of the neutron star (e.g. a model of the neutron star crust and superfluid components Meyers et al. 2021). However, for our purposes of exploring the detection of GWs via a state space formulation it will prove sufficiently accurate and appropriate.

2.2 Modulation of pulsar frequency due to a GW

In the presence of a GW, the $f(t)$ measured by an observer on Earth is different from that measured by an observer in the local NS reference frame. We want to determine how the GW influences the received frequency

2.2.1 *Plane GW perturbation*

We take a gravitational plane wave that perturbs a background Minkowski spacetime as

$$g_{\mu\nu} = \eta_{\mu\nu} + H_{\mu\nu} e^{i(\Omega(\bar{n}\cdot\bar{x} - t) + \Phi_0)} \tag{5}$$

for spatial coordinates $\bar{x}$, where the GW has a constant angular frequency Ω, propagates in the $\bar{n}$-direction and has a phase offset of Φ_0. We emphasise that Ω has no time dependence - we are concerned solely with monochromatic sources. Note that we are free to choose our coordinate system such that Φ_0 is the GW phase at $t = 0$ *at the Earth.*[2]. The amplitude tensor $H_{\mu\nu}$ has zero temporal components ($H_{0\mu} = H_{\mu 0} = 0$) whilst the spatial part is

$$H_{ij} = h_+ e^+_{ij}(\bar{n}) + h_\times e^\times_{ij}(\bar{n}) \tag{6}$$

where $h_{+,\times}$ are the polarisation amplitudes of the gravitational plane wave. The polarisation tensors $e^{+,\times}_{ij}$ are uniquely defined by the principal axes of the wave:

$$e^+_{ab}(\hat{\Omega}) = \hat{m}_a\hat{m}_b - \hat{n}_a\hat{n}_b \tag{7}$$

$$e^\times_{ab}(\hat{\Omega}) = \hat{m}_a\hat{n}_b + \hat{n}_a\hat{m}_b \tag{8}$$

which are in turn specified via the location of the GW source on the sky (via θ, ϕ coordinates) and the polarisation angle ψ

$$\begin{aligned}\vec{m} = &(\sin\phi\cos\psi - \sin\psi\cos\phi\cos\theta)\hat{x} \\ &- (\cos\phi\cos\psi + \sin\psi\sin\phi\cos\theta)\hat{y} \\ &+ (\sin\psi\sin\theta)\hat{z}\end{aligned} \tag{9}$$

$$\begin{aligned}\vec{n} = &(-\sin\phi\sin\psi - \cos\psi\cos\phi\cos\theta)\hat{x} \\ &+ (\cos\phi\sin\psi - \cos\psi\sin\phi\cos\theta)\hat{y} \\ &+ (\cos\psi\sin\theta)\hat{z}\end{aligned} \tag{10}$$

2.2.2 *Pulse frequency as a photon*

We will consider the pulse frequency as a photon with covariant 4-momentum p_μ. Generally, the frequency of a photon recorded by an observer with 4-velocity u^μ is

$$\nu = p_\alpha u^\alpha \tag{11}$$

We consider both our emitter and receiver to be stationary, such that

$$u^\alpha|_{\rm emitter} = u^\alpha|_{\rm receiver} = (1, 0, 0, 0) \tag{12}$$

Consequently the frequency can be directly identified with the temporal component of the covariant 4-momentum,

$$f = p_t \tag{13}$$

The expression for the evolution of the pulse frequency as measured by the observer on Earth is then,

$$p_t(t_1)|_{\rm Earth} = p_t(t_0)|_{\rm source} + \int_{t=t_0}^{t=t_1} \dot{p}_t \, dt \tag{14}$$

where the overdot denotes a derivative w.r.t. t. Since the influence of the GW perturbation on $\dot{p}_t$ is small, we can relate the source emission and receiver times as $t_1 = t_0 + d$ and consider the photon trajectory to be an unperturbed path. [3]

To complete our expression, we now just need to determine $\dot{p}_t$ and integrate it.

[2] **TK: This point is important, since the phase offset is then the same between multiple pulsars. See also Melatos 2022 PT12**
[3] **TK: See also e.g. Maggiore, Meltaos who takes the same approach...**

2.2.3 *Hamiltonian Mechanics*

The Hamiltonian in covariant notation can be written as

$$H(x^\mu, p_\mu) = \frac{1}{2} g_{\mu\nu} p^\mu p^\nu, \tag{15}$$

which if we substitute in our expression for the perturbed metric is

$$H = \frac{1}{2}\eta_{\mu\nu} p^\mu p^\nu + \frac{1}{2} H_{ij} p^i p^j e^{i(\Omega(\bar{n}\cdot\bar{x}-t)+\Phi_0)} \tag{16}$$

Now, Hamilton's equations are

$$\frac{dx^\mu}{d\lambda} = \frac{\partial H}{\partial p_\mu}, \quad \frac{dp_\mu}{d\lambda} = -\frac{\partial H}{\partial x^\mu} \tag{17}$$

for affine parameter λ. The derivative of the temporal component of the covariant momenta is then,

$$\frac{dp_t}{d\lambda} = -\frac{i\Omega}{2} H_{ij} p^i p^j e^{i(\Omega(\bar{n}\cdot\bar{x}-t))+\Phi_0} \tag{18}$$

[4]

Therefore the derivative w.r.t coordinate time t is,

$$\dot{p}_t = \frac{dp_t}{d\lambda}\left(\frac{dt}{d\lambda}\right)^{-1} = \frac{dp_t}{d\lambda}\left(\frac{1}{p^t}\right) \tag{19}$$

Note that $\dot{p}_t$ is entirely a function of the GW perturbation. In the Minkowski case the spacetime is stationary and so p_t should be conserved along the geodesic. It will prove useful to recognise that $p^\mu = \omega(1, -q^x, -q^y, -q^z)$ where $\bar{q}$ is the unit vector between the Earth and pulsar and ω is the *constant* photon angular frequency. Given the small effect of the GW perturbation, at first order we can identify ω as either the frequency at source or observer [5]. We will consider the pulsar locations to be constant with respect to the Earth. TK: **This may have already been "done" during the barycentreing when pulsar TOAs are generated, in which case q is the vector from the SSB to the pulsar**. Similarly we can express the spatial coordinates as $\bar{x}(t) = -\bar{q}t$.

Bringing this all together we can write $\dot{p}_t$ in a condensed form as,

$$\dot{p}_t = A e^{i\gamma t + \Phi_0} \tag{20}$$

where

$$\gamma = -\Omega(1 + \bar{n}\cdot\bar{q}) \tag{21}$$

[6] and

$$A = -\frac{i\Omega\omega}{2} H_{ij} q^i q^j \tag{22}$$

2.2.4 *Performing the integral*

The frequency shift experienced by the observer relative to the source due to a GW is then

$$p_t(\tau)|_{\text{Earth}} - p_t(\tau - d)|_{\text{source}} = A \int_{t=\tau-d}^{t=\tau} e^{i\gamma t + \Phi_0} dt \tag{23}$$

$$= \frac{-iA}{\gamma} e^{i\gamma\tau} e^{\Phi_0}[1 - e^{-i\gamma d}] \tag{24}$$

[4] **TK: This is equivalent to Melatos 2018, Eq 5 for the specific case of a GW propagating in the z-direction, with zero phase offset**.

[5] see Melatos 2022, PT16

[6] compare with Melatos 2022, PT11

We can write this more explicitly as,

$$p_t(\tau)|_{\text{Earth}} - p_t(\tau - d)|_{\text{source}} = \tag{25}$$

$$\frac{\omega}{2}\frac{H_{ij}q^i q^j}{(1+\hat{n}\cdot\hat{q})} e^{-i\Omega\tau(1+\bar{n}\cdot\bar{q})+\Phi_0}[1 - e^{i\Omega(1+\bar{n}\cdot\bar{q})d}] \tag{26}$$

or alternatively, with $h_{ij} = g_{ij} - \eta_{ij}$,

$$p_t(\tau)|_{\text{Earth}} - p_t(\tau - d)|_{\text{source}} = \frac{\omega}{2}\frac{h_{ij}q^i q^j}{(1+\hat{n}\cdot\hat{q})}[1 - e^{i\Omega(1+\bar{n}\cdot\bar{q})d}] \tag{27}$$

2.3 State-space structure

We now have a model for the evolution of the pulsar frequency states and the measured frequency timeseries. We can express the intrinsic frequency evolution, Eq. 4, in a alternative form as,

$$df = Af\,dt + N(t)dt + \sigma dB(t) \tag{28}$$

where $A = -\gamma$, $N(t) = \gamma(f_{\text{EM}}(0) + \dot{f}_{\text{EM}}(0)t) + \dot{f}_{\text{EM}}(0)$ and $dB(t)$ denotes increments of Brownian motion (Wiener process). This equation is easily identified as an Ornstein-Uhlenbeck process which has a general solution given by,

$$f(t) = e^{At}f(0) + \int_0^t e^{A(t-t')}N(t')dt' + \int_0^t e^{A(t-t')}\sigma dB(t') \tag{29}$$

If we move from a solution in continuous time to discrete time then

$$f(t_{i+1}) = Ff(t_i) + T_i + \eta_i \tag{30}$$

where

$$F_i = e^{A(t_{i+1}-t_i)} \tag{31}$$

$$T_i = \int_{t_i}^{t_{i+1}} e^{A(t_{i+1}-t')}N(t')dt' \tag{32}$$

$$\eta_i = \int_{t_i}^{t_{i+1}} e^{A(t_{i+1}-t')}\sigma dt' \tag{33}$$

Given the discrete solution $f(\bar{t})$ where $\bar{t} = (t_1, t_2, ..., t_N)$ the intrinsic frequency can be related to the measured frequency as

$$f_M = fg(\bar{\theta}, t) + N_M \tag{34}$$

where $g(\theta, t)$ ("measurement function")is a function of some parameters, $\bar{\theta}$ and time t, whilst N_M is a Gaussian measurement noise that satisfies

$$\langle N_M(t)N_M(t')\rangle = \Sigma^2\delta(t - t') \tag{35}$$

The measurement function follows from Eq. 27

$$g(\bar{\theta}, t) = 1 - \frac{1}{2}\frac{h_{ij}(t)q^i q^j}{1+\bar{n}\cdot\bar{q}}[1 - e^{i\Omega(1+\bar{n}\cdot\bar{q})d}] \tag{36}$$

or in a more concise form where we have switched to a trigonometric form of the equations,

$$g(\bar{\theta}, t) = 1 - A\cos(-\Omega t(1 + n\cdot q) + \Phi_0) \tag{37}$$

where

$$A = \frac{1}{2}\frac{H_{ij}q^i q^j}{1+\bar{n}\cdot\bar{q}}[1 - \cos(\Omega(1+\bar{n}\cdot\bar{q})d)] \tag{38}$$

3 DETECTION AND PARAMETER ESTIMATION

Given the proceeding state-space model we will now try to use this model to infer the unknown parameters of the system. Let's first review and categorise all the parameters of model. We can generally separate these into parameters which correspond to the intrinsic frequency evolution of the pulsar, the GW parameters and the noise parameters i.e.

$$\bar{\theta} = \bar{\theta}_{\rm PSR} \cup \bar{\theta}_{\rm GW} \cup \bar{\theta}_{\rm noise} \tag{39}$$

$$\bar{\theta}_{\rm PSR} = [\gamma, f_{\rm EM}(0), \dot{f}_{\rm EM}(0), d] \tag{40}$$

$$\bar{\theta}_{\rm GW} = [h_+, h_\times, \delta, \alpha, \psi, \Omega, \Phi_0] \tag{41}$$

$$\bar{\theta}_{\rm noise} = [\sigma, \Sigma] \tag{42}$$

Whilst the GW parameters are shared between measurements for each pulsar, the pulsar parameters are clearly not. For a PTA dataset of N pulsars we have $7+5N$ parameters to estimate. For now we will consider the measurement noise to be known, although in principle this too could be estimated. Note that whilst this is a large parameter space, in general the pulsar parameters are much better constrained than the GW parameters: for example we have rough estimates for the pulsar distances accurate to $\sim 10\%$, but we have no prior information on the source location.

We will use a Kalman filter in order to obtain likelihood estimates of the data given a set of parameters. We will now review the Kalman filter and the associated likelihood in Section before going on to discuss how to use nested sampling methods in conjunction with the filter for detection (model selection) and parameter estimation

3.1 Kalman Filtering

The Kalman filter (Kalman 1960) is a algorithmic technique for recovering a set of system state variables $\bar{x}$ given some noisy measurements $\bar{z}$. It is a common technique in signal processing that has also been applied more recently with great success in astrophysics (e.g. Meyers et al. 2021; Melatos et al. 2021). The linear Kalman filter operates on measurements that are related to states via a linear transformation

$$z = Hx + v \tag{43}$$

where H is the measurement matrix and v a Gaussian measurement noise. The underlying states are the solutions to the state-space equation

$$\dot{x} = Fx + Gu + w \tag{44}$$

where x are the state variables, F the system dynamics matrix, Gu the control matrix/vector and w a stochastic zero-mean process which . By comparison with the preceding equations Eqs. 28 - 38 it is immediately obvious how our state space model maps onto the Kalman filter structure. Specifically, our states are just the N intrinsic pulsar frequencies $\bar{x} = (f_1, f_2, ...f_N)$ whilst our measurements are the N measured pulse frequencies $\bar{z} = (f_1^{(M)}, f_2^{(M)}, ...f_N^{(M)})$. If we specialize to the case of constant time sampling between our observations, then for our formulation, the components that make up the Kalman filter are as follows:

$$F_i = F_{i+1} = e^{-\gamma \Delta t} \tag{45}$$

$$T_i = \int_{t_i}^{t_{i+1}} e^{A(t_{i+1}-t')} N(t') dt' \tag{46}$$

$$= f_{\rm EM}(0) + \dot{f}_{\rm EM}(0)(\Delta t + t_i) - e^{-\gamma \Delta t}(f_{\rm EM}(0) + \dot{f}_{\rm EM}(0) t_i) \tag{47}$$

$$H_i = 1 - A(\theta_{\rm GW}) \cos(-\Omega t_i (1 + n \cdot q) + \Phi_0) \tag{48}$$

and A is a constant that is given by Eq. 38. The Kalman filter includes the effect of process noise w and the measurement noise v via the definition of a process noise matrix $Q = E[ww^T]$ and a measurement noise matrix $R = E[vv^T]$, which have the discrete form,

$$Q_i \delta_{ij} = \langle \eta_i \eta_j^T \rangle = \frac{-\sigma^2}{2\gamma}\left(e^{-2\gamma\Delta t} - 1\right) \tag{49}$$

$$R_i = R_{i+1} = \Sigma^2 \tag{50}$$

For our formulation we are concerned only with the linear Kalman filter since the measurements are a linear function of the states and the state transitions are also linear. Extension to non-linear problems is straighforward using either an extended Kalman filter, the unscented Kalman filter or the particle filter. For a full review of the Kalman filter equations which may e unfamilar to some, we refer the reader to the appendix X of Melatos et al. (2021).

In order for the Kalman filter to function successfully, the parameters of the model which appear in teh various Kalman matrices must be correct. The Kalman filte rprovides an estiamte In this way,

here is an example for an arbitary GW and arbitrary pulsar with good and bad parameters

3.2 Nested Sampling

We can use NS for both param estimation and

4 VALIDATION ON SYNTHETIC DATA

4.1 PTA pulsars

Throughout this work it will be necessary to select a group of pulsars to make up our PTA. We will take the 47 pulsars that make up the NANOGrav PTA (Arzoumanian et al. 2020)

In order to proceed and explore how well this state-space formulation works, we will need to specify a selection of pulsars to make up our PTA. We will take the 47 pulsars that make up the NANOGrav PTA. For each pulsar, we need to specify the complete set of $\bar{\theta}_{\rm PSR}$ as well as σ. The parameters $f_{\rm EM}(0), \dot{f}_{\rm EM}(0), d$ are straightforward to set and can be read directly from the current "present day" best estimates of the pulsar frequency, derivative and distance.

4.2 Detection

4.3 Parameter Estimation

5 KALMAN FILTERING

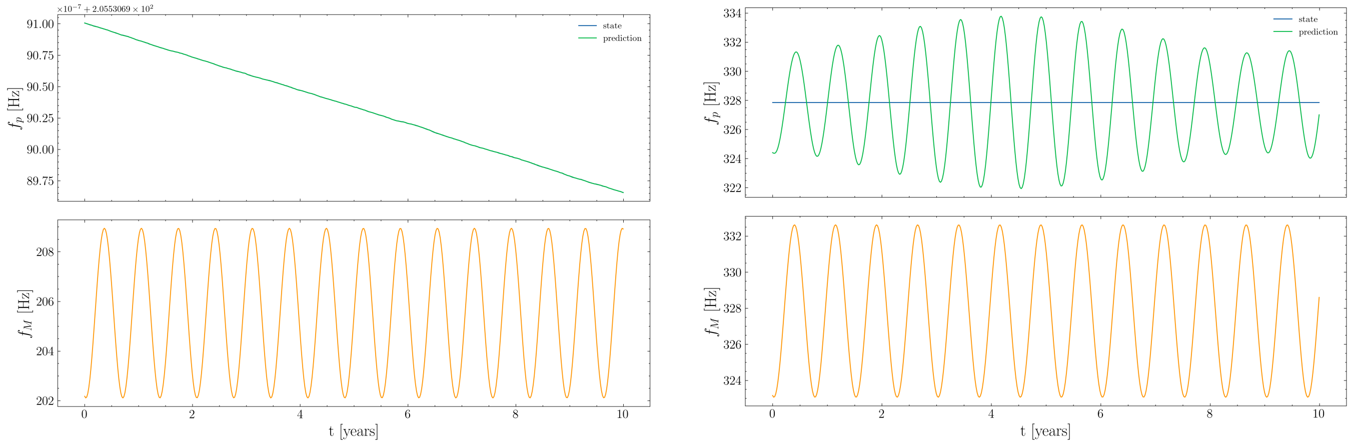
6 PARAMETER ESTIMATION

6.1 Nested sampling

7 DETECTION

The general structure of a Kalman state-space problem is

$$\dot{x} = f(x) + w \tag{51}$$



(a) (b)

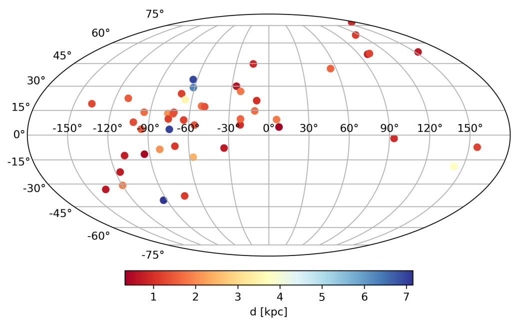


Figure 2. Spatial distribution and distances of NANOGrav pulsars

where x are the state variables, $f()$ a non-linear function of the states, and w a stochastic zero-mean process. The process noise matrix $Q = E(ww^T)$. The states are related to the measurement z via a non-linear measurement function $h()$

$$z = h(x) + v \tag{52}$$

where v is a stochastic zero-mean process and measurement noise matrix $R = E(vv^T)$.

This structure maps onto the preceding equations nicely. Our hidden state is just the intrinsic pulsar frequency, which evolves as,

$$\dot{f}_P = -\gamma f_P^n + \xi(t) \tag{53}$$

where n is a braking index (typical values $\sim 1-5$, we take a canonical value $= 3$) [7] γ a proportionality constant, and $\xi(t)$ represents a stochastic white noise process. Equation 36 can be used to relate the intrinsic pulsar frequency to that measured by an observer on Earth:

$$f_M = f_P(1 - X) + N_M \tag{54}$$

where X is the RHS of Eq. 36 and N_M a Gaussian measurement noise. An example of the evolution of the state and the measurement frequencies for our PTA pulsars can be seen in Fig. **??**

[7] See A. Vargas talk re anomalous braking indices. P.S. is there an arXiv preprint?

8 DISCRETISATION

This intrinsic frequency can be related to a measured frequency as

There are a few terms to unpack and define in this equation. $q(t)$ is the vector from the Earth to the pulsar, n the propagation direction of the GW, Ω the (constant) angular frequency of the GW and d the Earth-pulsar distance. $h_{ij}(t)$ is the metric perturbation due to the GW = $g_{ij} - \eta_{ij}$. It is given by the familiar plane-wave relation:

$$h_{ij}(t) = H_{ij} e^{(i(\bar{k}\cdot\bar{x} - \Omega t + \Phi_0))} \tag{55}$$

where $\bar{k}$ is the GW 3-wavevector $= \Omega\bar{n}$ and $x = -\bar{q}t$ (photon propagates from pulsar to Earth), and for phase offset (GW phase at Earth when $t = 0$) Φ_0. We can also write this as,

$$h_{ij}(t) = H_{ij} e^{(-i\Omega t(1+\bar{n}\cdot\bar{q}) + \Phi_0))} \tag{56}$$

The amplitude tensor H_{ij} is

$$H_{ij} = h_+ e^+_{ij}(\bar{n}, \psi) + h_\times e^\times_{ij}(\bar{n}, \psi) \tag{57}$$

where $h_{+,\times}$ are the constant amplitudes of the gravitational plane wave, and $e^{+,\times}_{ij}(\bar{n}, \psi)$ are the polarisation tensors which are uniquely defined by the principal axes of the GW. ψ is the polarisation angle of the GW.

Going forward,

Bringing this together, and adopting a trigonometric form of the equations, we can express the measurement equation as

8.1 Parameters of the model

We can also express the measurement equation generally as,
Kalman filtering works as follows
you can see that it maps nicel onto our state separation

9 METHODS

There are two potential methods we can take

(i) Let the states just be the frequencies $\bar{x} = (f)$. We have a linear equation for both the state evolution and the measurement matrix. Both of these depend on the parameters θ. Use the likelihood output by a standard Kalman filter to run a nested sampler and try to recover θ.

(ii) Let the states be the frequencies and all the unknown parameters $\bar{x} = (f, \bar{\theta}_{\rm GW}, \bar{\theta}_{\rm PSR}, \bar{\theta}_{\rm noise})$. Our state evolution is now linear but our measurement matrix is non-linear - a function of the states(parameters). Use a non-linear estimator such as a EKF/UKF to try to recover all of the states at once.

9.1 Method 1

In the case where the states are just the intrinsic pulsar frequencies, we can write the ODEs in matrix form as

$$d\bar{X} = \bar{A}\bar{X}dt + \bar{N}(t)dt + \bar{\Sigma}d\bar{B}(t) \tag{58}$$

where $\bar{A} = \text{diag}(\gamma_1, \gamma_2, ...)$, $\bar{X} = \text{diag}(f_1, f_2, ...)$, $\bar{N} = \text{diag}(\gamma_1[a_1 + b_1 t] + b_1, ...)$ and we have let $a = f_{EM}(0)$, $b = \dot{f}_{\rm EM}(0)$.

9.2 References

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