## **Linear Gaussian**

#### **Basic Model**

$$egin{aligned} \mathbf{x}_{t+1} &= \mathbf{A}\mathbf{x}_t + \mathbf{w}_t &= \mathbf{A}\mathbf{x}_t + \mathbf{w}_ullet & \mathbf{w}_ullet \sim \mathcal{N}(0, \mathbf{Q}) \ \mathbf{y}_t &= \mathbf{C}\mathbf{x}_t + \mathbf{v}_t &= \mathbf{C}\mathbf{x}_t + \mathbf{v}_ullet & \mathbf{v}_ullet \sim \mathcal{N}(0, \mathbf{R}) \end{aligned}$$

## EM algorithm: Learning



$$\log \int_{\mathbf{X}} P(\mathbf{Y}, \mathbf{X} \mid \theta) d\mathbf{X} = \log \int_{\mathbf{X}} Q(\mathbf{X}) \frac{P(\mathbf{X}, \mathbf{Y} \mid \theta)}{Q(\mathbf{X})} d\mathbf{X}$$

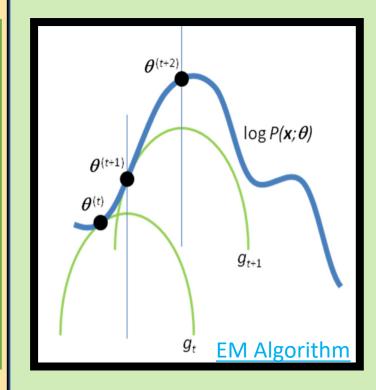
$$\geq \int_{\mathbf{X}} Q(\mathbf{X}) \log \frac{P(\mathbf{X}, \mathbf{Y} \mid \theta)}{Q(\mathbf{X})} d\mathbf{X}$$

$$= \int_{\mathbf{X}} Q(\mathbf{X}) \log P(\mathbf{X}, \mathbf{Y} \mid \theta) d\mathbf{X} - \int_{\mathbf{X}} Q(\mathbf{X}) \log Q(\mathbf{X}) d\mathbf{X}$$

$$= \mathcal{F}(Q, \theta)$$

E step  $Q_{k+1} \leftarrow rg \max_{Q} \mathcal{F}(Q, heta_k)$ 

 $\mathsf{M} \ \mathsf{step} \qquad heta_{k+1} \leftarrow rg \max_{ heta} \mathcal{F}(Q_{k+1}, heta)$ 



## Filtering & smoothing

$$egin{aligned} P(\mathbf{x}_t \mid \{\mathbf{y}_1, \dots, \mathbf{y}_t\}) \ P(\mathbf{x}_t \mid \{\mathbf{y}_1, \dots, \mathbf{y}_ au\}) \end{aligned}$$

# Gaussian

#### **Basic Model**

$$egin{aligned} \mathbf{x}_{t+1} &= \mathbf{A}\mathbf{x}_t + \mathbf{w}_t = \mathbf{A}\mathbf{x}_t + \mathbf{w}_ullet & \mathbf{w}_ullet \sim \mathcal{N}(0, \mathbf{Q}) \ \mathbf{y}_t &= \mathbf{C}\mathbf{x}_t + \mathbf{v}_t = \mathbf{C}\mathbf{x}_t + \mathbf{v}_ullet & \mathbf{v}_ullet \sim \mathcal{N}(0, \mathbf{R}) \end{aligned}$$

#### Static data modelling (variants)

$$egin{aligned} \mathbf{x}_{ullet} &= \mathbf{w}_{ullet} & \mathbf{w}_{ullet} \sim \mathcal{N}(\mathbf{0}, \mathbf{I}) \ \mathbf{y}_{ullet} &= \mathbf{C} \mathbf{x}_{ullet} + \mathbf{v}_{ullet} & \mathbf{v}_{ullet} \sim \mathcal{N}(\mathbf{0}, \mathbf{R}) \end{aligned}$$

### **Factor Analysis**

$$R = egin{bmatrix} r_1 & 0 & 0 & \dots & 0 \ 0 & r_2 & 0 & \dots & 0 \ 0 & 0 & r_{
m m} & \dots & 0 \ dots & dots & dots & \ddots & dots \ 0 & 0 & 0 & \dots & r_{
m s} \ \end{pmatrix}$$

**SPCA** 

PCA

$$\mathbf{R} = \epsilon \mathbf{I} \qquad \mathbf{R} = \lim_{\epsilon o 0} \epsilon \mathbf{I}$$

## Time-series modelling

#### **Kalman Filter**

$$egin{aligned} \mathbf{x}_{t+1} &= \mathbf{A}\mathbf{x}_t + \mathbf{w}_t = \mathbf{A}\mathbf{x}_t + \mathbf{w}_ullet & \mathbf{w}_ullet \sim \mathcal{N}(\mathbf{0}, \mathbf{Q}) \ \mathbf{y}_t &= \mathbf{C}\mathbf{x}_t + \mathbf{v}_t = \mathbf{C}\mathbf{x}_t + \mathbf{v}_ullet & \mathbf{v}_ullet \sim \mathcal{N}(\mathbf{0}, \mathbf{R}) \end{aligned}$$

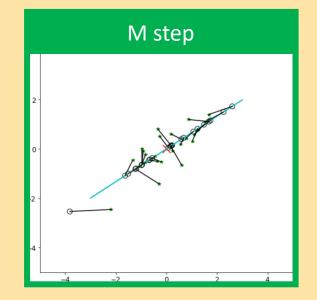
#### **PCA**

$$\mathbf{x}_ullet = \mathbf{w}_ullet \qquad \mathbf{w}_ullet \sim \mathcal{N}(\mathbf{0}, \mathbf{I})$$

$$\mathbf{y}_ullet = \mathbf{C}\mathbf{x}_ullet + \mathbf{v}_ullet \quad \mathbf{v}_ullet \sim \mathcal{N}(\mathbf{0}, \mathbf{R})$$

$$\mathbf{R} = \lim_{\epsilon o 0} \epsilon \mathbf{I}$$

# E step

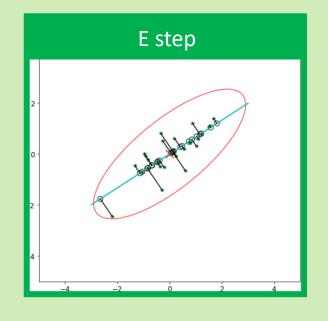


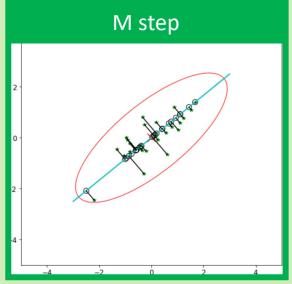
Init: C = [1,0]Generate X

M: update C

# **PCA Simulation**

E: 
$$\mathbf{X} = \left(\mathbf{C}^T\mathbf{C}\right)^{-1}\mathbf{C}^T\mathbf{Y}$$
M:  $\mathbf{C}^{\mathrm{new}} = \mathbf{Y}\mathbf{X}^T\left(\mathbf{X}\mathbf{X}^T\right)^{-1}$ 

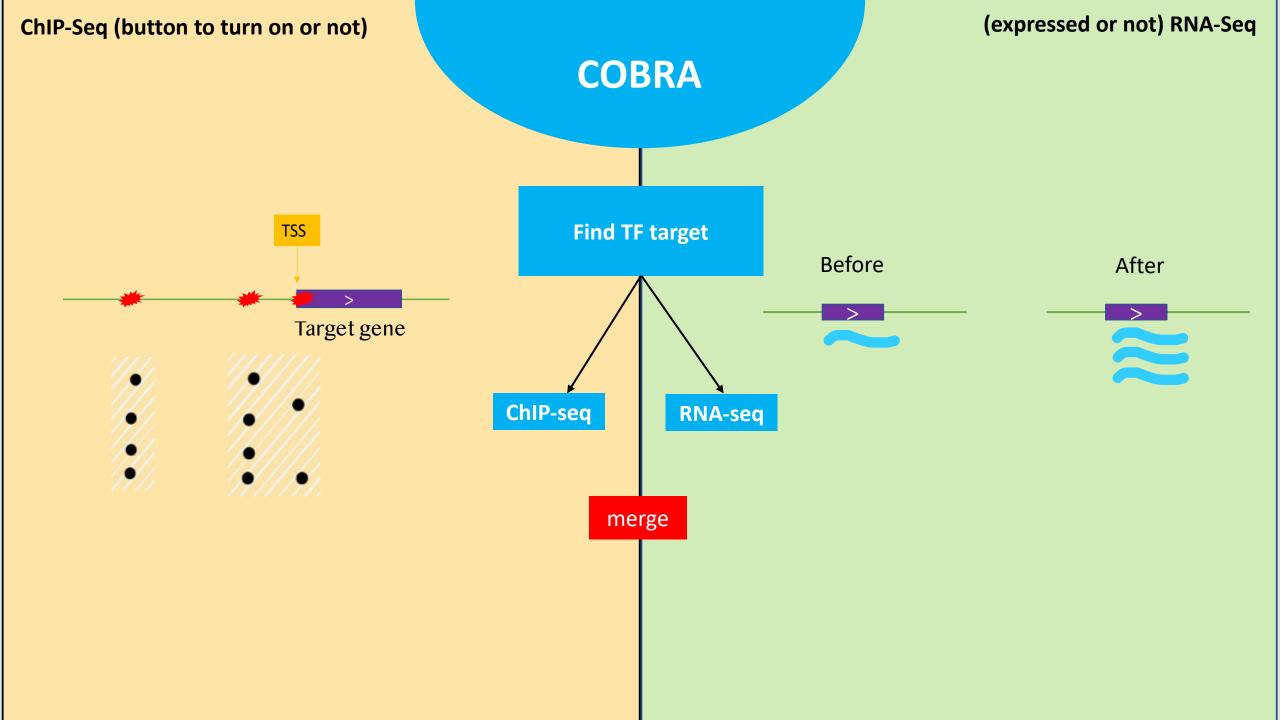




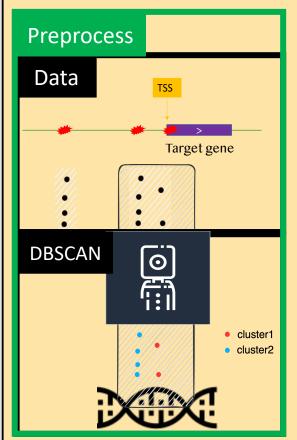
E: update X

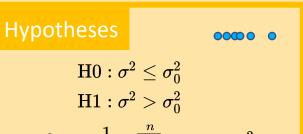
M: update C

code



## **COBRA**



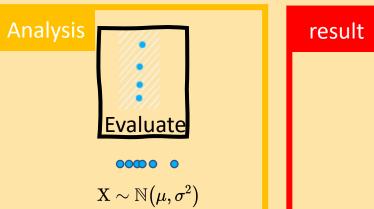


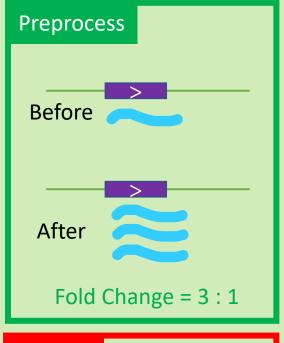
$$\hat{\sigma}^2 = rac{1}{n-1} \sum_{i=1}^n ig(X_i - ar{X}ig)^2$$

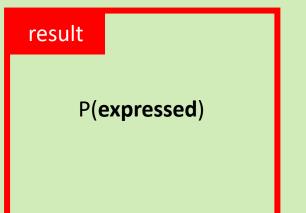
Test statistic 
$$\sim \chi^2_{n-1}$$

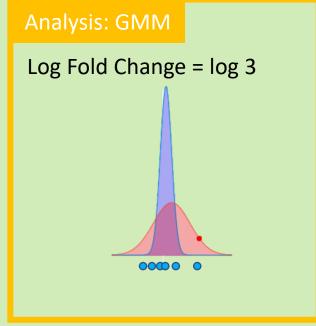
$$\chi^2 = rac{1}{\sigma_0^2} \sum_{i=1}^n ig( X_i - ar{X} ig)^2 = rac{(n-1)\hat{\sigma}^2}{\sigma_0^2}$$

P(turn on)









P(turn on) P(expressed)

Independent

# **COBRA**

