Estimation Theory

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- An **observation** is defined as:

$$y = h(x) + w$$

where $x \in \mathbb{R}^n$ and $y \in \mathbb{R}^m$ denote the unknown vector and the measurement vector. $h : \mathbb{R}^n \to \mathbb{R}^m$ is a function of x and w is the observation noise with the power density $f_w(w)$.
- It is assumed that x is a random variable with an a priori power density $f_x(x)$ before the observation.
- The goal is to compute the "best" estimation of x using the observation.

Optimal Estimation

- The optimal estimation $\hat{x}$ is defined based on a cost function J:
- $$\hat{x}_{opt} = \arg\min_{\hat{x}} E[J(x - \hat{x})]$$

  Some typical cost functions:
  - Minimum Mean Square Error ($\hat{x}_{MMSE}$):
  - $$J(x - \hat{x}) = (x - \hat{x})^{\mathrm{T}} W (x - \hat{x}), \quad W > 0$$

    Absolute Value ($\hat{x}_{ABS}$):
  - $$J(x - \hat{x}) = |x - \hat{x}|$$

    Maximum a Posteriori ($\hat{x}_{MAP}$):
- $$J(x - \hat{x}) = \begin{cases} 0 & \text{if } |x - \hat{x}| \leq \epsilon \\ 1 & \text{if } |x - \hat{x}| > \epsilon \end{cases}, \quad \epsilon \to 0$$

  It can be shown that:
- $$\hat{x}_{MMSE}(y) = E[x|y]$$

  $$\int_{-\infty}^{\hat{x}_{ABS}(y)} f_{x|y}(x|y)\, dx = \int_{\hat{x}_{ABS}(y)}^{+\infty} f_{x|y}(x|y)\, dx$$

  $$\hat{x}_{MAP} = \arg\max_{x} f_{x|y}(x|y)$$

  If the a posteriori density function $f_{x|y}(x|y)$ has only one maximum and it is symmetric with respect to $E[x|y]$ then all the above estimates are equal to $E[x|y]$.

- In fact, assuming these conditions for $f_{x|y}(x|y)$, $E(x|y)$ is the optimal estimation for any cost function J if $J(0) = 0$ and $J(x - \hat{x})$ is nondecreasing with distance (**Sherman's Theorem**).
- **Maximum Likelihood Estimation:** $\hat{x}_{ML}$ is the value of x that maximizes the probability of observing y:
- $$\hat{x}_{ML}(y) = \arg\max_x f_{y|x}(y|x)$$

  It can be shown that $\hat{x}_{ML} = \hat{x}_{MAP}$ if there is no a priori information about x.

Linear Gaussian Observation

- Consider the following observation: $y = Ax + Bw$ where $w \sim \mathcal{N}(0, I_r)$ is a Gaussian random vector and matrices $A_{m\times n}$ and $B_{m\times r}$ are known.
- In this observation, x is estimable if A has full column rank otherwise there will be infinite solutions for the problem.
- If BB^{T} is invertible, then:
- $$\begin{aligned} f_{y|x}(y|x) = & \frac{1}{(2\pi)^{n/2}|BB^{\mathrm{T}}|^{1/2}} \\ & \times \exp\left(-\frac{1}{2}\left[(y - Ax)^{\mathrm{T}}(BB^{\mathrm{T}})^{-1}(y - Ax)\right]\right) \end{aligned}$$

  The maximum likelihood estimation can be computed as:
- $$\begin{aligned} \hat{x}_{ML} &= \arg\min_x (y - Ax)^{\mathrm{T}}(BB^{\mathrm{T}})^{-1}(y - Ax) \\ &= (A^{\mathrm{T}}(BB^{\mathrm{T}})^{-1}A)^{-1}A^{\mathrm{T}}(BB^{\mathrm{T}})^{-1}y \end{aligned}$$

  It is very interesting that $\hat{x}_{ML}$ is the Weighted Least Square (WLS) solution to the following equation: $y = Ax$ with the weight matrix $W = BB^{\mathrm{T}}$ i.e.
- $$\hat{x}_{WLS} = \arg\min_x (y - Ax)^{\mathrm{T}}W(y - Ax)$$

  $\hat{x}_{ML}$ is an unbiased estimation:
- $$\begin{aligned} b(x) &= E[x - \hat{x}_{ML}|x] \\ &= E\left[(A^{\mathrm{T}}(BB^{\mathrm{T}})^{-1}A)^{-1}A^{\mathrm{T}}(BB^{\mathrm{T}})^{-1}y - x \mid x\right] = 0 \end{aligned}$$

  The covariance of the estimation error is:
- $$P_e(X) = E[(x - \hat{x}_{ML})(x - \hat{x}_{ML})^{\mathrm{T}}|x] = (A^{\mathrm{T}}(BB^{\mathrm{T}})^{-1}A)^{-1}$$

  $\hat{x}_{ML}$ is *efficient* in the sense of Cramér Rao bound.

- **Example:** Consider the following linear Gaussian observation: $y = ax + w$ where a is a nonzero real number and $w \sim \mathcal{N}(0, r)$ is the observation noise.

- **Maximum a Posteriori Estimation:** To compute $\hat{x}_{MAP}$, it is assumed that the a priori density of x is Gaussian with mean m_x and variance p_x:

- $$x \sim \mathcal{N}(m_x, p_x)$$

  The conditions of Sherman's Theorem is satisfied and therefore:

- $$\begin{aligned} \hat{x}_{MAP} &= E[x|y] \\ &= m_x + \frac{p_{xy}}{p_y}(y - m_y) \\ &= m_x + \frac{ap_x}{a^2 p_x + r}(y - am_x) \\ &= \frac{ap_x y + m_x r}{a^2 p_x + r} \end{aligned}$$

  Estimation bias:

- $$b_{MAP} = E[x - \hat{x}_{MAP}] = m_x - \frac{ap_x e[y] + rm_x}{a^2 p_x + r} = m_x - \frac{a^2 p_x m_x + rm_x}{a^2 p_x + r} = 0$$

  Estimation error covariance:

- $$p_{MAP} = E[(x - \hat{x}_{MAP})^2] = p_x - \frac{a^2 p_x^2}{a^2 p_x + r} = \frac{p_x r}{a^2 p_x + r}$$

  Maximum Likelihood Estimation: For this example, we have:

- $$f_{y|x}(y|x) = f_w(y - ax) = \frac{1}{\sqrt{2\pi r}} \exp\left(-\frac{(y - ax)^2}{2r}\right)$$

  With this information:

- $$\hat{x}_{ML} = \arg\max_x f_{y|x}(y|x) = \frac{y}{a}$$

  Estimation bias:

- $$b_{ML} = E[x - \hat{x}_{ML}|x] = x - \frac{ax}{x} = 0$$

  Estimation error covariance:

- $$p_{ML} = E[(x - \hat{x}_{ML})^2|x] = E\left[\left(x - \frac{ax + w}{a}\right)^2\right] = \frac{r}{a^2}$$

  Comparing x_{MAP} and x_{ML}, we have:

  $$\lim_{p_x \to +\infty} \hat{x}_{MAP} = \hat{x}_{ML}$$

  It means that if there is no a priori information about x, the two estimations are equal.

- For the error covariance, we have:

- $$\frac{1}{p_{MAP}} = \frac{1}{p_{ML}} + \frac{1}{p_x}$$

  In other words, information after observation is the sum of information of the observation and information before the observation.

- Estimation error covariance:

- $$\lim_{p_x \to +\infty} \hat{p}_{MAP} = \hat{p}_{ML}$$

  It is possible to include a priori information in maximum likelihood estimation.

- A priori distribution of x, $\mathcal{N}(m_x, p_x)$, can be rewritten as the following observation: $m_x = x + v$ where $v \sim \mathcal{N}(0, p_x)$ is the observation noise.

- **Combined observation**: $z = Ax + u$ where:

- $$z = \begin{bmatrix} m_x \\ y \end{bmatrix}, A = \begin{bmatrix} 1 & 0 \\ 0 & a \end{bmatrix}, u = \begin{bmatrix} v \\ w \end{bmatrix}$$

  The assumption is that v and w are *independent*. Therefore:

- $$u \sim \mathcal{N}\left(0, \begin{bmatrix} p_x & 0 \\ 0 & r \end{bmatrix}\right)$$

  Maximum likelihood estimation:

- $$\begin{aligned} \hat{x}_{MLp}(z) &= \arg\max_x f_{z|x}(z|x) \\ &= \arg\min_x \left(\frac{(m_x - x)^2}{p_x} + \frac{(y - ax)^2}{r} \right) \\ &= \frac{a p_x y + m_x r}{a^2 p_x + r} = \hat{x}_{MAP} \end{aligned}$$

  $\hat{x}_{MLp}$ is unbiased and has the same error covariance as $\hat{x}_{MAP}$.

- Therefore $\hat{x}_{MLp}$ and $\hat{x}_{MAP}$ are equivalent.

Standard Kalman Filter

- Consider the following linear system:

  $$\begin{cases} x(k+1) &= A(k)x(k) + w(k) \\ y(k) &= C(k)x(k) + v(k) \end{cases}$$

  where $x(k) \in \mathbb{R}^n$, $y(k) \in \mathbb{R}^m$ denote the state vector and measurement vector at time t_k.

- $w(k) \sim \mathcal{N}(0, Q(k))$ and $v(k) \sim \mathcal{N}(0, R(k))$ are independent Gaussian white noise processes where $R(k)$ is invertible.

- It is assumed that there is an a priori estimation of x, denoted by $\hat{x}^-(k)$, which is assumed to be unbiased with a Gaussian estimation error, independent of w and v:

$$e^-(k) \sim \mathcal{N}(0, P^-(k))$$

where $P^-(k)$ is invertible.

- The Kalman filter is a recursive algorithm to compute the state estimation.

- **Output Measurement:** Information in $\hat{x}^-(k)$ and $y(k)$ can be written as the following observation:

$$\begin{bmatrix} \hat{x}^-(k) \\ y(k) \end{bmatrix} = \begin{bmatrix} I \\ C(k) \end{bmatrix} x(k) + \begin{bmatrix} e^-(k) \\ v(k) \end{bmatrix}$$

Considering the independence of $e^-(k)$ and $v(k)$, we have:

- $$\begin{bmatrix} e^-(k) \\ v(k) \end{bmatrix} \sim \mathcal{N}\left(0, \begin{bmatrix} P^-(k) & 0 \\ 0 & R(k) \end{bmatrix}\right)$$

Using the Weighted Least Square (WLS) and matrix inversion formula:

- $$(A + BD^{-1}C)^{-1} = A^{-1} - A^{-1}B(D + CA^{-1}B)^{-1}CA^{-1}$$

Assuming:

- $$K(k) = P^-(k)C^{\mathrm{T}}(k)[C(k)P^-(k)C^{\mathrm{T}}(k) + R(k)]^{-1}$$

We have:

- $$\hat{x}(k) = \hat{x}^-(k) + K(k)(y(k) - C(k)\hat{x}^-(k))$$

State estimation is the sum of a priori estimation and a multiplicand of output prediction error. Since:

- $$\hat{y}^-(k) = C(k)\hat{x}^-(k)$$

$K(k)$ is the Kalman filter gain.

- Estimation error covariance:

- $$P(k) = (I - K(k)C(k))P^-(k)$$

Information:

$$\hat{x}(k) = x(k) + e(k)$$

where $e(k) \sim \mathcal{N}(0, P(k))$

- **State Update:** To complete a recursive algorithm, we need to compute $\hat{x}^-(k+1)$ and $P^-(k+1)$.

- Information:

$$\begin{aligned} \hat{x}(k) &= x(k) + e(k) \\ 0 &= \begin{bmatrix} -I & A(k) \end{bmatrix} \begin{bmatrix} x(k+1) \\ x(k) \end{bmatrix} + w(k) \end{aligned}$$

- By *removing* $x(k)$ from the above observation, we have:
- $$A(k)\hat{x}(k) = x(k+1) + A(k)e(k) - w(k)$$
  It is easy to see:
- $$\hat{x}^{-}(k+1) = A(k)\hat{x}(k)$$
  Estimation error:
- $$e^{-}(k+1) = A(k)e(k) - w(k)$$
  Estimation covariance:
  $$P^{-}(k+1) = A(k)P(k)A^{\mathrm{T}}(k) + Q(k)$$

Summary:

- Initial Conditions: $\hat{x}^{-}(k)$ and its error covariance $P^{-}(k)$.
- Gain Calculation:
- $$K(k) = P^{-}(k)C^{\mathrm{T}}(k)[C(k)P^{-}(k)C^{\mathrm{T}}(k) + R(k)]^{-1}$$
  $\hat{x}(k)$:
- $$\begin{aligned} \hat{x}(k) &= \hat{x}^{-}(k) + K(k)(y(k) - C(k)\hat{x}^{-}(k)) \\ P(k) &= (I - K(k)C(k))P^{-}(k) \end{aligned}$$
  $\hat{x}^{-}(k+1)$:
- $$\begin{aligned} \hat{x}^{-}(k+1) &= A(k)\hat{x}(k) \\ P^{-}(k+1) &= A(k)P(k)A^{\mathrm{T}}(k) + Q(k) \end{aligned}$$
  Go to gain calculation and continue the loop for $k+1$.

Remarks:

- Estimation residue:
- $$\gamma(k) = y(k) - C(k)\hat{x}^{-}(k)$$
  Residue covariance:
- $$P_{\gamma}(k) = C(k)P^{-}(k)C^{\mathrm{T}}(k) + R(k)$$
  The residue signal is used for monitoring the performance of Kalman filter.
- Modeling error, round-off error, disturbance, correlation between input and measurement noise, and other factors might cause a biased and colored residue.
- The residue signal can be used in Fault Detection and Isolation (FDI).
- The standard Kalman filter is not numerically robust because it contains matrix inversion. For example, the calculated error covariance matrix might not be positive definite because of computational errors.

- There are different implementations of Kalman filter to improve the standard Kalman filter in the following aspects:
    - Computational efficiency
    - Dealing with disturbance or unknown inputs
    - Handling singular systems (difference algebraic equations)