Kalman Filtering with miscFuncs

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Abstract
This vignette provides a program template for use with the kFadvance function.

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1. Introduction
The purpose of this vignette is to provide a template R functions for implementing the Kalman Filter and for parameter estimation for Gaussian dynamic linear models. The functions should provide a FLEXIBLE basis on which to build R code for optimal linear filtering.

After loading miscFuncs, the templates below can be printed to the R console (and hence copied and pasted into an editor) using KFtemplates:

```r
library(miscFuncs)
KFtemplates()
```

2. The Statistical Model
Let $\Theta_t$ be the state vector and $Y_t$ be the observation vector at time $t$.

The function kFadvance works with COLUMN VECTORS.

The statistical model is:

\begin{align*}
\Theta_t &= A_t \Theta_{t-1} + B_t + C_t \epsilon_t, \quad \epsilon_t \sim N(0, W_t) \\
Y_t &= D_t \Theta_{t-1} + E_t + F_t \nu_t, \quad \nu_t \sim N(0, V_t)
\end{align*}

Suppose $\Theta_t$ has dimension $n \times 1$ and $Y_t$ has dimension $m \times 1$, then the matrices in the above have dimensions:
The matrix $D_t$ acts like a design matrix in ordinary least squares regression. The user must also specify priors (aka initial values) for $\Theta$ in the form of a prior mean $n \times 1$ matrix (called $X_{post}$ in the code below\footnote{this might seem a strange name, given that it is the prior, but in the template code below, this object is overwritten and eventually becomes the posterior mean.}) and a prior variance $n \times n$ matrix (called $V_{post}$ in the code below).

Typically some, or all of $A_t$, $B_t$, $C_t$, $W_t$, $D_t$, $E_t$, $F_t$, $V_t$ will be parametrised. Part of the goal of filtering will typically involve estimating these parameters by maximum likelihood. To allow optimisation to work well, model parameters should be free to roam between real numbers. For example if a parameter represents a variance (ie should only take positive values) then the inside the $KFfit$ function, use for example $\sigma \leftarrow \exp(\text{param}[1])$ or if the parameter is on the $[0,1]$ then use the inverse logistic function, $\exp(\text{param}[2])/(1+\exp(\text{param}[2]))$.

The template for parameter estimation comes later.

3. Fitting the Model to Some Data

This section provides template code for Kalman filtering under the above model.

```r
# see vignette for notation
KFfit <- function( param, # model parameters
data, # a matrix containing the data ie Y
... # delete this line and include other arguments to be passed

  # opti=FALSE, # set this to FALSE if not estimating parameters, otherwise,
  # if parametes have already been estimated, then set to TRUE
  history.means=FALSE, # whether to save a matrix of filtered $E(\Theta_t)$
  history.vars=FALSE, # whether to save a list of filtered $V(\Theta_t)$
  prior.mean=NULL, # optional prior mean. column vector. # Normally set
  prior.var=NULL, # optional prior mean. matrix. # these inside the code
  fit=FALSE, # whether to return a matrix of fitted values
  se.fit=FALSE, # whether to return the standard error of the fitted values
  se.predict=FALSE, # whether to return the prediction standard error =
  # se(fitted values) + observation variance $V_t$
  noisy=TRUE, # whether to print a progress bar, useful.
  na.res=FALSE) # whether to use NA handling. set to TRUE if any Y is NA

start <- Sys.time()

if(se.predict & !se.fit){
  stop("Must have se.fit=TRUE in order to compute se.predict") # leads to a computational saving
}

# Here, I would suggest creating dummy names for your parameters eg
# sigma.obs <- exp(model.param[1])

T <- dim(data)[1] # ASSUMES OBSERVATIONS ARE IN A (T x m) matrix, ie row t contains the data for time t.
# Note this is important for when KFadvance is called later
```
if(is.null(prior.mean)){
    Xpost <- DEFINE PRIOR MEAN HERE
} else{
    Xpost <- prior.mean
}

if(is.null(prior.var)){
    Vpost <- DEFINE PRIOR VARIANCE HERE
} else{
    Vpost <- prior.var
}

if (history.means){
    Xrec <- Xpost
} if(history.vars){
    Vrec[[1]] <- Vpost
}

# delete or complete the following rows as necessary, also appears in the loop that follows
A <- IF A IS FIXED OVER TIME THEN DEFINE IT HERE
B <- IF B IS FIXED OVER TIME THEN DEFINE IT HERE
C <- IF C IS FIXED OVER TIME THEN DEFINE IT HERE
W <- IF W IS FIXED OVER TIME THEN DEFINE IT HERE
D <- IF D IS FIXED OVER TIME THEN DEFINE IT HERE
E <- IF E IS FIXED OVER TIME THEN DEFINE IT HERE
F <- IF F IS FIXED OVER TIME THEN DEFINE IT HERE
V <- IF V IS FIXED OVER TIME THEN DEFINE IT HERE

loglik <- 0
fitmat <- c()
sefitmat <- c()
sepredictmat <- c()

if(noisy){
    pb <- txtProgressBar(min=1,max=T,style=3)
    sepredictmat <- c()
}

for(t in 1:T){
    # delete or complete the following rows as necessary
    A <- IF A IS TIME-VARYING THEN DEFINE IT HERE
    B <- IF B IS TIME-VARYING THEN DEFINE IT HERE
    C <- IF C IS TIME-VARYING THEN DEFINE IT HERE
    W <- IF W IS TIME-VARYING THEN DEFINE IT HERE
    D <- IF D IS TIME-VARYING THEN DEFINE IT HERE
    E <- IF E IS TIME-VARYING THEN DEFINE IT HERE
    F <- IF F IS TIME-VARYING THEN DEFINE IT HERE
    V <- IF V IS TIME-VARYING THEN DEFINE IT HERE

    # this bit calls KF advance
    new <- KFadvance(obs=data[t,],oldmean=Xpost,oldvar=Vpost,A=A,B=B,C=C,D=Dt,E=E,F=F,W=W,V=V,marglik=TRUE,log=TRUE,na.rm=na.rm)
    Xpost <- new$mean
    Vpost <- new$var
    if(t==1) { # used when this function is called iteratively one step at a time
        running.mean <- Xpost
        running.var <- Vpost
    }
    loglik <- loglik + new$mlik

    if (history.means){
        Xrec <- cbind(Xrec,Xpost)
    }
    if(history.vars){
        Vrec[[t+1]] <- Vpost # since first entry is the prior
    }
    if(fit){
        fitmat <- cbind(fitmat,D%*%Xpost + E)
    }
    if(se.fit){
        sefitmat <- cbind(sefitmat,sqrt(diag(D%*%Vpost%*%t(D))))
    }
    if(se.predict){
        sepredictmat <- cbind(sepredictmat,sqrt((sefitmat[,ncol(sefitmat)]^2+diag(F%*%V%*%t(F))))
    }

    if(noisy){
        setTxtProgressBar(pb,t)
    }
}

if(noisy){
4. Parameter Estimation

This section provides template code for parameter estimation in Kalman filtering.

```r
KFparest <- function( data, # data ie Y ...){ # delete and paste in OTHER ARGUMENTS TO BE PASSED TO KFfit
  start <- Sys.time()
  inits <- PUT INITIAL VALUES FOR PARAMETER VECTOR HERE
  # use optim to find optimal parameters
  oppars <- optim(inits, # delete and paste in OTHER ARGUMENTS TO BE PASSED TO KFfit
                  data=data, # delete and paste in OTHER ARGUMENTS TO BE PASSED TO KFfit
                  KFfit, # TO BE PASSED TO KFfit
                  optim=TRUE,
                  control=list(trace=100))

  end <- Sys.time()
  cat("Time Taken",difftime(end,start,units="mins")," mins")
  cat("\n")
  return(oppars)
}
```

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