Forgetting-based Estimation of Stationary Parameters in Marginalized Particle Framework

¹Šmídl Václav

Particle filtering is a popular approximation of Bayesian filtering, i.e. on-line recursive evaluation of posterior distribution of unknown time-varying quantities. Its success is documented by a range of applications in object tracking, navigation, video processing, etc. A known weakness of the particle filtering is its inability to estimate stationary or slowly-varying quantities, which are typically called parameters. Theoretical studies suggest that this task is perhaps impossible as the posterior density degenerates in time [1, 4].

The marginalized particle filtering arise for specific problems that allow analytical marginalization over a part of the unknowns. If the marginalization is over the stationary parameters and the resulting marginal density has sufficient statistics, it is known as particle learning. In effect, each particle carries sufficient statistics of the parameters. This approach was believed to mitigate the problems with stationary parameters [2], however, extensions of the previous analytical results to this case points out the same degeneracy as in the non-marginalized case [3].

A heuristic approach to avoid degeneracy of the posterior density is the use of classical forgetting techniques developed for recursive estimation with sufficient statistics [5]. This approach has been shown to avoid the degeneracy problem in simulation [6]. In this contribution, we will demonstrate the degeneracy problem on some simulated examples. Various forgetting techniques, such as scheduling of the forgetting factor, will be compared. An informal theoretical justification of the use of the forgetting approach will be given as well as its potential limitations. In summary, estimation of the stationary parameters in particle filtering (as well as marginalized particle filtering) is still an open problem. Application of the forgetting technique allows to estimate slowly varying parameters. Its application to stationary parameters is suboptimal, however, it may be sufficient for many practical applications.

References

- O. Cappé, R. Douc, É. Moulines, and C. Robert. On the convergence of the Monte Carlo maximum likelihood method for latent variable models. *Scandinavian Journal of Statistics*, 29(4):615–635, 2002.
- [2] C.M. Carvalho, M. Johannes, H.F. Lopes, and N. Polson. Particle learning and smoothing. *Statistical Science*, 25(1):88–106, 2010.
- [3] N. Chopin, A. Iacobucci, J-M. Marin, K. Mengersen, Ch. Robert, R. Ryder, and Ch. Schäfer. On particle learning. ArXiv e-prints, jun 2010.
- [4] N. Kantas, A. Doucet, S.S. Singh, and J.M. Maciejowski. An overview of sequential Monte Carlo methods for parameter estimation in general state-space models. 2009.
- [5] R. Kulhavý and M. B. Zarrop. On a general concept of forgetting. International Journal of Control, 58(4):905–924, 1993.
- [6] S. Saha, E. Özkan, V. Šmídl, and F. Gustafsson. Marginalized particle filters for Bayesian estimation of noise parameters. In *Proceedings of the 13th International Conference on Information Fusion*, Edinburgh, UK, 2010.

1

¹Institute of Information Theory and Automation, department of Adaptive Systems, *smidl@utia.cas.cz*