

# Contents

<b>Preface</b>	<b>xi</b>
<b>1 Probability Theory</b>	<b>1</b>
1.1 Probability Theory as a Set of Outcomes . . . . .	1
1.2 Set Theory . . . . .	6
1.3 Probability Space and the Probability Measure . . . . .	8
1.4 Algebras of Sets and Probability Space . . . . .	9
1.5 Key Concepts in Probability Theory . . . . .	13
1.6 Exercises . . . . .	18
<b>2 Random Variables and Stochastic Processes</b>	<b>25</b>
2.1 Random Variables . . . . .	25
2.2 Probability Distribution Function . . . . .	28
2.3 Probability Density Function . . . . .	31
2.4 Probabilistic Concepts Applied to Random Variables . . . . .	35
2.5 Functions of a Random Variable . . . . .	37
2.6 Expectations and Moments of a Random Variable . . . . .	40
2.7 Characteristic Functions . . . . .	46
2.8 Conditional Expectations and Conditional Probabilities . . . . .	53
2.9 Stochastic Processes . . . . .	59
2.10 Gauss–Markov Processes . . . . .	63
2.11 Nonlinear Stochastic Difference Equations . . . . .	65
2.12 Exercises . . . . .	66
<b>3 Conditional Expectations and Discrete-Time Kalman Filtering</b>	<b>81</b>
3.1 Minimum Variance Estimation . . . . .	81
3.2 Conditional Estimate of a Gaussian Random Vector with Additive Gaussian Noise . . . . .	88
3.2.1 Simplification of the Argument of the Exponential . . . . .	90
3.2.2 Simplification of the Coefficient of the Exponential . . . . .	91
3.2.3 Processing Measurements Sequentially . . . . .	91
3.2.4 Statistical Independence of the Error and the Estimate . . . . .	93
3.3 Maximum Likelihood Estimation . . . . .	94
3.4 The Discrete-Time Kalman Filter: Conditional Mean Estimator . . . . .	95

3.5	“Tuning” a Kalman Filter . . . . .	106
3.6	Discrete-Time Nonlinear Filtering . . . . .	109
3.6.1	Dynamic Propagation . . . . .	110
3.6.2	Measurement Update . . . . .	110
3.7	Exercises . . . . .	111
<b>4</b>	<b>Least Squares, the Orthogonal Projection Lemma, and Discrete-Time Kalman Filtering</b>	<b>119</b>
4.1	Linear Least Squares . . . . .	119
4.2	The Orthogonal Projection Lemma . . . . .	129
4.3	Extensions of Least Squares Theory . . . . .	134
4.4	Nonlinear Least Squares: Newton–Gauss Iteration . . . . .	136
4.5	Deriving the Kalman Filter via the Orthogonal Projection Lemma . . . . .	140
4.6	Exercises . . . . .	145
<b>5</b>	<b>Stochastic Processes and Stochastic Calculus</b>	<b>153</b>
5.1	Random Walk and Brownian Motion . . . . .	153
5.2	Mean-Square Calculus . . . . .	160
5.3	Wiener Integrals . . . . .	168
5.4	Itô Integrals . . . . .	171
5.5	Second-Order Itô Integrals . . . . .	178
5.6	Stochastic Differential Equations and Exponentials . . . . .	180
5.7	The Itô Stochastic Differential . . . . .	182
5.8	Continuous-Time Gauss–Markov Processes . . . . .	186
5.9	Propagation of the Probability Density Function . . . . .	190
5.10	Exercises . . . . .	192
<b>6</b>	<b>Continuous-Time Gauss–Markov Systems: Continuous-Time Kalman Filter, Stationarity, Power Spectral Density, and the Wiener Filter</b>	<b>197</b>
6.1	The Continuous-Time Kalman Filter (Kalman–Bucy Filter) . . . . .	197
6.2	Properties of the Continuous-Time Riccati Equation . . . . .	202
6.3	Stationarity . . . . .	204
6.4	Power Spectral Densities . . . . .	207
6.4.1	Fourier Transforms . . . . .	207
6.4.2	Fourier Analysis Applied to Random Processes . . . . .	208
6.4.3	Ergodic Random Processes . . . . .	214
6.5	Continuous-Time Linear Systems Driven by Stationary Signals . . . . .	215
6.6	Discrete-Time Linear Systems Driven by Stationary Random Processes . . . . .	220
6.7	The Steady-State Kalman Filter: The Wiener Filter . . . . .	223
6.7.1	The Wiener Filtering Problem Statement . . . . .	223
6.7.2	Solving the Wiener–Hopf Equation . . . . .	225
6.7.3	Noncausal Filter . . . . .	226
6.7.4	The Causal Filter . . . . .	228
6.7.5	Wiener Filtering by Orthogonal Projections . . . . .	233
6.8	Exercises . . . . .	234

<b>7</b>	<b>The Extended Kalman Filter</b>	<b>241</b>
7.1	Linearized Kalman Filtering . . . . .	241
7.1.1	Continuous-Time Theory . . . . .	241
7.1.2	Discrete-Time Version . . . . .	243
7.2	The Extended Kalman Filter . . . . .	244
7.3	The Iterative Extended Kalman Filter . . . . .	245
7.4	Filter Divergence . . . . .	249
7.4.1	What is Divergence? . . . . .	249
7.4.2	The Role of Process Noise Weighting in the Steady State . . . . .	249
7.4.3	An Analysis of Divergence . . . . .	252
7.5	Exercises . . . . .	255
 <b>8</b>	 <b>A Selection of Results from Estimation Theory</b>	 <b>263</b>
8.1	Continuous-Time Colored-Noise Filter . . . . .	263
8.2	Optimal Smoothing and Filtering in Continuous Time . . . . .	267
8.3	Discrete-Time Smoothing and Maximum Likelihood Estimation . . . . .	271
8.4	Linear Exponential Gaussian Estimation . . . . .	273
8.4.1	The LEG Estimator and Sherman's Theorem . . . . .	273
8.4.2	Statistical Properties of the LEG Estimator and the Kalman Filter . . . . .	275
8.5	Estimation with State-Dependent Noise . . . . .	277
8.5.1	General Theory . . . . .	277
8.5.2	Application to Phase-Lock Loops . . . . .	279
8.6	Exercises . . . . .	284
 <b>9</b>	 <b>Stochastic Control and the Linear Quadratic Gaussian Control Problem</b>	 <b>289</b>
9.1	Dynamic Programming: An Illustration . . . . .	289
9.2	Stochastic Dynamical System . . . . .	291
9.2.1	Stochastic Control Problem with Perfect Observation . . . . .	292
9.3	Dynamic Programming Algorithm . . . . .	292
9.4	Stochastic LQ Problems with Perfect Information . . . . .	295
9.4.1	Application of the Dynamic Programming Algorithm . . . . .	295
9.5	Dynamic Programming with Partial Information . . . . .	297
9.5.1	Sufficient Statistics . . . . .	299
9.6	The Discrete-Time LQG Problem with Partial Information . . . . .	300
9.6.1	The Discrete-Time LQG Solution . . . . .	300
9.6.2	Insights into the Partial Information, Discrete-Time LQG Solution . . . . .	304
9.6.3	Stability Properties of the LQG Controller with Partial Information . . . . .	305
9.7	The Continuous-Time LQG Problem . . . . .	305
9.7.1	Dynamic Programming for Continuous-Time Markov Processes . . . . .	305
9.7.2	The LQG Problem with Complete Information . . . . .	307
9.7.3	LQ Problem with State- and Control-Dependent Noise . . . . .	309
9.7.4	The LQG Problem with Partial Information . . . . .	310

9.8	Stationary Optimal Control . . . . .	317
9.8.1	General Conditions . . . . .	317
9.8.2	The Stationary LQG Controller . . . . .	320
9.9	LQG Control with Loop Transfer Recovery . . . . .	321
9.9.1	The Guaranteed Gain Margins of LQ Optimal Controllers . . . . .	322
9.9.2	Deriving the LQG/LTR Controller . . . . .	326
9.10	Exercises . . . . .	330
<b>10</b>	<b>Linear Exponential Gaussian Control and Estimation</b>	<b>335</b>
10.1	Discrete-Time LEG Control . . . . .	335
10.1.1	Formulation of the LEG Problem . . . . .	335
10.1.2	Solution Methodology and Properties of the LEG Problem . . . . .	336
10.1.3	LEG Controller Solution . . . . .	341
10.1.4	The LEG Estimator . . . . .	351
10.2	Terminal Guidance: A Special Continuous-Time LEG Problem . . . . .	355
10.3	Continuous-Time LEG Control . . . . .	362
10.4	LEG Controllers and $H_\infty$ . . . . .	364
10.4.1	The LEG Controller and Its Relationship with the Disturbance Attenuation Problem . . . . .	365
10.4.2	The Time-Invariant LEG Estimator Transformed into the $H_\infty$ Estimator . . . . .	366
10.4.3	The $H_\infty$ Measure and the $H_\infty$ Robustness Bound . . . . .	368
10.4.4	The Time-Invariant, Infinite-Time LEG Controller and Its Rela- tionship with $H_\infty$ . . . . .	369
10.4.5	Example . . . . .	371
10.5	Exercises . . . . .	372
	Appendix A. Proof of Lemma 10.1 . . . . .	373
	Appendix B. Proof of Lemma 10.2 . . . . .	374
	<b>Bibliography</b>	<b>377</b>
	<b>Index</b>	<b>381</b>