Optimally bounded Interval Kalman filter
Quoc Hung Lu, Soheib Fergani, Carine Jauberthie, Francoise Le Gall

To cite this version:
Quoc Hung Lu, Soheib Fergani, Carine Jauberthie, Francoise Le Gall. Optimally bounded Interval Kalman filter. 2019 IEEE 58th Conference on Decision and Control (CDC), Dec 2019, Nice, France. pp.379-384, 10.1109/CDC40024.2019.9028918 . hal-03300095

HAL Id: hal-03300095
https://hal.laas.fr/hal-03300095
Submitted on 8 Jun 2023

HAL is a multi-disciplinary open access archive for the deposit and dissemination of scientific research documents, whether they are published or not. The documents may come from teaching and research institutions in France or abroad, or from public or private research centers.

L’archive ouverte pluridisciplinaire HAL, est destinée au dépôt et à la diffusion de documents scientifiques de niveau recherche, publiés ou non, émanant des établissements d’enseignement et de recherche français ou étrangers, des laboratoires publics ou privés.
Abstract—This paper is concerned with the optimization of the upper bounds of the interval covariance matrices [1]. This filter is applied to discrete time linear systems subject to mixed uncertainties (combining bounded and stochastic uncertainties), in terms of observations and noises (mainly sensors limitations). It uses interval analysis in order to provide the optimal bound of the state estimation error covariance. Based on that, an optimal state estimation enclosing the set of all possible solutions w.r.t admissible uncertainties is performed. In this article, theorems and lemmas proving the optimality of the proposed solution are provided. Simulations on an example show the efficiency of the developed interval estimation.

I. INTRODUCTION

State and parameter estimation are topics of utmost importance when dealing with system control. Indeed, obtaining accurate estimations can lead to great improvements in the systems performances. One of the largely used estimation strategy is Kalman filtering. Recently, several extensions of this technique have been presented to deal with the system uncertainties. In [2] and [3], novel designs of optimal robust Kalman filters have been introduced to deal with parameter uncertainties for discrete time-varying systems subject to norm-bounded uncertainties. The main idea of these designs is trying to minimize an upper bound on the estimation error covariance for any acceptable modeling uncertainties. The drawback of these methods is the large conservatism when dealing with too many uncertainties. To overcome this limitation, a solution would be to consider the resulting model matrices, considering the Gaussian noise, as intervals containing all admissible values of parameters. Unfortunately, a singularity problem may appear in interval matrix inversion.

For the last few years, authors have been working on the singularity problem of the interval matrix inversion. While in [1], the solution proposed by using the upper bound of the interval matrix to be inverted is not guaranteed (the solution set may not include all the classical Kalman filter solutions consistent with the bounded uncertainties represented in the system), [4] presented an improved interval Kalman filter (iIKF). It solves the interval matrix inversion problem with the set inversion algorithm SIVIA (Set Inversion Via Interval Analysis) and constraint satisfaction problems (CSP) (see [5]). After that, works focused on reducing both the conservatism and the high computational cost of these algorithms in [6] and [7], [8] introduced a joint Zonotopic and Gaussian Kalman filter to handle the two paradigms of bounded dis-

Optimally bounded Interval Kalman filter

Quoc-Hung Lu1, Soheib Fergani1, Carine Jauberthie1, Françoise Le Gall1

1 LAAS-CNRS, Université de Toulouse, CNRS, UPS, Toulouse, France. Corresponding author: qhlu@laas.fr
In the case of Hermitian matrices, this order is known as the Loewner (partial) order (ref. [9], [10]). Recall that a partial order \( R \) satisfies the properties: i) \( aRa \) (Reflexivity); ii) If \( aRb \) and \( bRa \) then \( a = b \) (Anti-symmetry); iii) If \( aRb \) and \( bRc \) then \( aRc \) (Transitivity).

We also extend this partial order to the notion of bounds for a non empty set \( \Omega \) of real squared matrices. If a real squared matrix \( K \) dominates all matrices contained in \( \Omega \), then \( K \) is an upper bound of \( \Omega \), denoted \( \Omega \preceq K \). In other words,

\[
\Omega \preceq K \iff M \preceq K, \ \forall M \in \Omega.
\]

If \( K \) and \( L \) are two upper bounds of \( \Omega \), then we say that \( K \) is better than \( L \) if and only if the norm of \( K \) is smaller than or equal to the norm of \( L \) depending on the choice of norms in definition 3.

An real interval matrix is a matrix which components are intervals. Let \( [M] \) be an \( n \times n \) real interval matrix. We denote:

a) \( M \in [M] \) to indicate a punctual matrix \( M \) included in \( [M] \).

b) \( S([M]) \triangleq \{ M \in [M] : M = M^T \} \), the set of symmetric matrices included in \( [M] \).

c) \( S_+(([M])) \triangleq \{ M \in S([M]) : M \succeq 0 \} \), the set of symmetric positive semi-definite matrices included in \( [M] \).

d) \( BS([M]) \triangleq \{ K \in S(n) : S([M]) \succeq K \} \), the set of symmetric upper bounds of \( S([M]) \).

e) \( BS_+(([M])) \triangleq \{ K \in S_+(n) : S_+(([M])) \succeq K \} \), the set of symmetric positive semi-definite upper bounds of \( S_+(([M])) \).

In the sequel, we assume that \( S_+(([M])) \) is non empty. For any \( n \times n \) matrix \( A \), we use the notations \( \sigma_i(A) \), \( \lambda_i(A) \) \((i = 1, \ldots, n)\) to indicate respectively the singular values and eigenvalues of \( A \) among which \( \sigma_{\text{max}}(A) \) and \( \lambda_{\text{max}}(A) \) are the corresponding maximum values.

**Definition 3**: Let \( A \in \mathbb{R}^{n \times n} \) and \( x = (x_1, \ldots, x_n) \in \mathbb{R}^n \). Vector norm and matrix norms are defined as follow. ([10])

a) The Euclidian vector norm: \( \|x\|_2 \triangleq \sqrt{\sum_{i=1}^{n} x_i^2} \).

b) The nuclear norm:

\[
\|A\|_* \triangleq \sum_{i=1}^{n} \sigma_i(A) = \sum_{i=1}^{n} \sqrt{\lambda_i(A^T A)}.
\]

c) The operator norm:

\[
\|A\| \triangleq \sigma_{\text{max}}(A) = \sqrt{\lambda_{\text{max}}(A^T A)}.
\]

d) The Frobenius norm:

\[
\|A\|_F \triangleq \sqrt{\sum_{i=1}^{n} \sigma_i^2(A)} = \sqrt{\sum_{i=1}^{n} \lambda_i(A^T A)} = \sqrt{\text{tr}(A^T A)} = \sqrt{\sum_{i,j=1}^{n} |A_{ij}|^2}.
\]

**Remark 1**: If \( A \succeq 0 \) then \( \sigma_i(A) = \lambda_i(A), \ \forall i = 1, \ldots, n \), so

- \( \|A\|_* = \sum_{i=1}^{n} \lambda_i(A) = \text{tr}(A) \),
- \( \|A\| = \lambda_{\text{max}}(A) \),
- \( \|A\|_F = \sqrt{\sum_{i=1}^{n} \lambda_i^2(A)} = \sqrt{\text{tr}(A^2)} = \sqrt{\sum_{i,j=1}^{n} |A_{ij}|^2} \).

**A. Properties**

First of all, we note that \( S(n) \) is a vector (sub-)space (of \( \mathbb{R}^{n \times n} \)) since \( \alpha M + \beta N \in S(n), \ \forall M, N \in S(n), \forall \alpha, \beta \in \mathbb{R} \) and \( S_+(n) \) is a convex cone since the above expression is just satisfied for \( \alpha, \beta > 0 \).

**Proposition 1**: Let \( M \in S(n) \) such that \( \lambda_{\text{max}}(M) < \infty \). Then \( M \succeq \alpha I \) if and only if \( \alpha \geq \lambda_{\text{max}}(M) \).

**Proposition 2**: Let \( A, B \in S_+(n) \) such that \( A \succeq B \) then

\[
\|A\| \leq \|B\| \text{ and } \|A\|_* \leq \|B\|_*.
\]

For all the following propositions and corollary, let \( [M] \) be an \( n \times n \) real interval bounded symmetric matrix.

**Proposition 3**: The following properties are verified:

a) \( S([M]) \) is compact in the norm vector space \( S(n) \).

b) \( S_+(([M])) \) is a compact subset of \( S([M]) \).

c) \( \Gamma \triangleq \{ \gamma = \|M\| : M \in S_+(([M])) \} \) is compact in \( \mathbb{R} \).

d) \( \sup_{M \in S_+(([M])} \{ \lambda_{\text{max}}(M) \} < \infty \).

**Proof**:

a) The upper triangular part of matrix \( [M] \) is composed of \( m = \frac{n^2+n}{2} \) intervals \( I_1, \ldots, I_m \). We can construct a continuous function \( f \) from \( I_1 \times \ldots \times I_m \in \mathbb{R}^{n \times n} \). Then, since \( I_1 \times \ldots \times I_m \) is compact in \( \mathbb{R}^m \), the image \( f(I_1 \times \ldots \times I_m) = S([M]) \) is also compact in \( S(n) \).

The construction of \( f \) is given by: \( f = \psi \circ \phi \) with \( \phi : I_1 \times \ldots \times I_m \rightarrow \mathbb{R}^{n \times n} \) verifying \( x = (x_1, \ldots, x_m) \mapsto \phi(x) = N = 
\[
\begin{bmatrix}
x_1 & x_2 & \cdots & x_n \\
0 & x_{n+1} & \cdots & x_{2n-1} \\
\vdots & \ddots & \ddots & \vdots \\
0 & \cdots & 0 & x_m
\end{bmatrix}
\]
and \( \psi : \mathbb{R}^{n \times n} \rightarrow \mathbb{R}^{n \times n} \) verifying

\[
N \mapsto \psi(N) = N + N^T - \text{diag}(N)
\]
are two continuous functions.

b) It is only necessary to prove that \( S_+(([M])) \) is closed in \( S(n) \), and the result is concluded by the property: If \( K \) is compact in a topological space \( X \) and if \( F \) is closed in \( X \) with \( F \subseteq K \), then \( F \) is compact.

We assume that \( \{M_k\}_k \) is a sequence in \( S_+(([M])) \) converging to \( M_\infty \in S(n) \) and prove that \( M_\infty \in S_+(([M])) \), i.e. \( M_\infty \in [M] \) and \( M_\infty \succeq 0 \).
The result is induced by extreme value theorem using the compactness of $\Gamma$. In the sequel, we denote $\text{Proposition 4:}$ 

$S_+([M])$ is compact, then $\Gamma$ is also compact.

d) The result is induced by extreme value theorem using the compactness of $\Gamma$.

In the sequel, we denote $\alpha_s := \sup_{M \in S_+([M])} \{\lambda_{\text{max}}(M)\}$.

\textbf{Proposition 4:}  
a) $S_+([M]) \leq \alpha I$ if and only if $\alpha \geq \alpha_s$, 
b) $E := \{M \in S_+([M]) : \text{diag}(M) = \text{diag}(\text{sup}([M]))\}$ is the non empty set of maximal elements of $S_+([M])$.

c) If $E^c := S_+([M])\backslash E$ contains at least two elements $M, N$ such that $M_{kl} \neq N_{kl}$ for some tuple $(k, l)$ : $k \neq l$, $(k, l = 1, ..., n)$, then $S_+([M])$ has no greatest element.

\textbf{Proof:}

a) Thanks to proposition 1, we get $\alpha \geq \alpha_s$ if and only if $M \leq \alpha I, \forall M \in S_+([M])$. The proposition 4a) is concluded.

b) First, let $M \in S_+([M])$ (which is non empty). If $M \in E$ then $E$ is non empty. If $M \notin E$, i.e. $\text{diag}(M) \neq \text{diag}(\text{sup}([M]))$, we denote $\tilde{M} = M + \Delta$ where $\Delta = -\text{diag}(M) + \text{diag}(\text{sup}([M]))$. Then $\tilde{M} \in S_+([M])$ and satisfies $\text{diag}(M) = \text{diag}(\text{sup}([M]))$. So $E$ is non empty since $\tilde{M} \in E$. In addition, no matrix $M \in S_+([M])$ such that $\text{diag}(M) \neq \text{diag}(\text{sup}([M]))$ is a maximal element of $S_+([M])$ since such a matrix $M$ is always dominated by another matrix $\tilde{M} \in E$. In other words, any maximal element of $S_+([M])$ (if it exists) must belong to $E$.

Next, we prove that any element of $E$ is a maximal element of $S_+([M])$. In fact, no matrix $M \in S_+([M])\backslash E$ dominates an element $P \in E$ since $\text{tr}(P) \neq \text{tr}(M)$ (using proposition 2). Hence, we prove that any two elements in $E$ do not dominate each other. Let $P, Q \in E$ such that $P \neq Q$ and $L = P - Q$. Then $L$ satisfies $L_{ii} = 0$ and $L_{ij} = P_{ij} - Q_{ij}, \forall i, j = 1, ..., n$. To obtain $Q \leq P$, it is necessary:

$\forall u = (u_1, ..., u_n) \neq 0$, 

$u^T Lu = 2 \sum_{i<j} u_i u_j L_{ij} \geq 0$.

This expression must be satisfied for all following choices of vector $u$. Let $p, q = 1, ..., n$ and $p < q$. By choosing

$u = \tilde{u} = (\delta_p(1) - \delta_q(1), ..., \delta_p(n) - \delta_q(n))$,

and

$u = u = (\delta_p(1) - \delta_q(1), ..., \delta_p(n) - \delta_q(n))$,

where $\delta_c(l)$ is the Kronecker delta, it is necessary that:

$\tilde{u}^T \tilde{L} \tilde{u} = 2 \sum_{i<j} (\delta_p(i) + \delta_q(i) (\delta_p(j) + \delta_q(j)) L_{ij} = 2 \tilde{L}_{pq} \geq 0$,

then, $\tilde{L}_{pq} = 0, \forall p, q = 1, ..., n$ and $p < q$, which implies a contradiction.

c) Let $M, N \in E^c$ such that $M_{kl} \neq N_{kl}$ for some tuple $(k, l)$ : $k \neq l$, $(k, l = 1, ..., n)$. Let $P = M - \text{diag}(M) + \text{diag}(\text{sup}([M]))$ and $Q = N - \text{diag}(N) + \text{diag}(\text{sup}([M]))$. Then $P$ and $Q$ are such that $P, Q \in S_+([M])$, $P \neq Q$ and $\text{diag}(P) = \text{diag}(Q) = \text{diag}(\text{sup}([M]))$. Hence $P$ and $Q$ belong to $E$ and are two different maximal elements of $S_+([M])$. This implies that $S_+([M])$ does not have the greatest element.

\textbf{Corollary 1:} There exists a matrix $N^* \in E$ such that $\lambda_{\text{max}}(N^*) = \alpha_s$.

\textbf{Proposition 5:} Let $K \in B S_+([M])$. Then:

a) $\alpha_s I$ is the optimal upper bound of $S_+([M])$ in the set $B S_+([M])$ in the sense of operator norm minimization.

b) $\alpha_s I$ is the optimal upper bound of $S_+([M])$ in the set of upper bounds $K \in B S_+([M])$ such that

$\frac{\lambda_1(K) + ... + \lambda_n(K)}{n} \geq \alpha_s$.

in the sense of nuclear norm minimization.

In the following, the notation $\text{mid}([M])$ stands for the matrix of center points.

\textbf{Proposition 6:} Let $\text{Max}$ be a matrix determined by

$Max_{ij} = \begin{cases} 
\sup([M])_{ij}, & \text{if } \text{mid}([M])_{ij} \geq 0 \\
\inf([M])_{ij}, & \text{otherwise} 
\end{cases}$

then $\sup_{M \in S_+([M])} \{||M||_F\} \leq ||\text{Max}||_F$ and $\alpha_s \leq ||\text{Max}||_F$. In addition, if $\text{Max} \geq 0$, then

$\lambda_{\text{max}}(\text{Max}) \leq \alpha_s \leq ||\text{Max}||_F$. 
III. MAIN RESULTS

We have proved that a non empty set $S_+([M])$ can be dominated by an upper bound of the form $\alpha I$ ($\alpha > 0$). Furthermore, we pointed out that the particular upper bound $\alpha I$ is the optimal bound for $S_+([M])$ among other bounds in $BS_+([M])$ according to the operator norm. And if we use the nuclear norm as a criterion, $\alpha I$ is also the optimal bound in a rather large subset of $BS_+([M])$: the set of matrices $K \in BS_+([M])$ such that

$$\frac{\lambda_1(K) + \ldots + \lambda_n(K)}{n} \geq \alpha_s.$$ 

The use of this particular upper bound ensures on one hand a solution to the singularity problem of the interval matrix inversion as well as the conservatism of the algorithms, and on the other hand an appreciable reduction of the computation time. This fact is verified in a numerical simulation in which the use of this kind of upper bound reduces by over 40% the computation time and ensures more consistent estimate intervals. In addition, by using an appropriate choice of coefficients ($\beta_k$ and $\sigma_k$) the traces of estimated covariance error bounds are well controlled. Although we did not find the exact value of $\alpha_s$ but a bound for it, the numerical simulation showed that we can rather use its upper bound ($\|Max\|_F$) to obtain the desired results presented in section IV.

From a statistical point of view, we used this particular upper bound as a covariance matrix of a multi-dimensional (Gaussian) noise which components are mutually independent. In other words, in our problem, all covariance matrices included in an interval $[Q]$ can be represented by the one of a multi-dimensional variable which components are mutually independent. These results are used to develop our new Optimal Upper Bound Interval Kalman Filter.

A. Optimal Upper Bound Interval Kalman Filter

Consider the linear discrete time dynamic system represented by the states and measures equations

$$\begin{align*}
    x_k &= A_k x_{k-1} + B_k u_k + w_k \\
y_k &= C_k x_k + v_k
\end{align*}$$

(1)

where the notations are usual for the classic Kalman filter: $x_k \in \mathbb{R}^{n_x}$ state variables, $y_k \in \mathbb{R}^{n_y}$ state noises, $u_k \in \mathbb{R}^{n_u}$ inputs, $w_k \in \mathbb{R}^{n_x}$ state noises, $v_k \in \mathbb{R}^{n_y}$ measure noises. Matrices $A_k, B_k, C_k$ are unknown, deterministic and included in bounded interval matrices $[A], [B], [C]$ respectively. $w_k, v_k$ are centered Gaussian with covariance matrices $Q_k$ and $R_k$ included respectively in bounded interval matrices $[Q]$ and $[R]$. The initial state $x_0$ is also Gaussian. In addition, $x_0, \{w_1 : w_k\}$ and $\{v_1 : v_k\}$ are assumed to be mutually independent.

Our aim is to estimate intervals $[\hat{x}_k]$ which contain state variables $x_k$. Moreover, each value $\hat{x}_k \in [\hat{x}_k]$ can be considered as a point estimate of $x_k$. By applying the Kalman classic filter calculations, we obtain, $\forall A_k \in [A], \forall C_k \in [C], \forall Q_k \in [Q], \forall R_k \in [R], \forall \hat{x}_k \in [\hat{x}_k]$ and $\forall k \geq 1$:

$$P_{k|k} = E[(x_k - \hat{x}_k)(x_k - \hat{x}_k)^T] = (I - K_kC_k)(A_kP_{k-1|k-1}A_k^T + Q_k)(I - K_kC_k)^T + K_kR_kK_k^T.$$ 

(2)

Let $S_+([P_{k|k-1}]) \leq \alpha_k I$ and $S_+([R]) \leq \gamma I$, then

$$P_{k|k} \leq \alpha_k(I - K_kC_k)(I - K_kC_k)^T + \gamma K_kK_k^T.$$ 

By applying the same strategy as the one in [7], we obtain, $\forall A_k \in [A], \forall C_k \in [C], \forall Q_k \in [Q], \forall R_k \in [R], \forall \hat{x}_k \in [\hat{x}_k]$ and $\forall k \geq 1$:

$$P_{k|k} \leq \alpha_k \left(1 + \sum_{i=1}^{n_u} \sum_{j=1}^{n_v} \beta_{ij,k}^{-1} T_{ij} \right) (I - K_k m)(I - K_k m)^T + \gamma K_kK_k^T,$$

where

$$\gamma = \frac{\alpha_k}{n_x} \left(\sum_{i=1}^{n_u} \sum_{j=1}^{n_v} T_{ij} \right)^2 + \frac{\alpha_k}{n_x} \left(\sum_{i=1}^{n_u} \sum_{j=1}^{n_v} T_{ij} \right)^2 (I - K_k m)^T + \gamma K_kK_k^T,$$

for any $\beta_{ij,k} > 0, \sigma_{ijuv,k} = \sigma_k > 0$ and where $m = \text{mid}([C])$, $r_{ij} = \text{rad}([C_{ij}])$ and $T_{ij} = 1$ if $\text{rad}([C])_{ij} > 0$ and null otherwise. Note that the notations $\text{mid}([C])$ and $\text{rad}([C])$ stand for the matrix of center points and the matrix of radius of $[C]$ respectively.

We choose $\beta_{ij,k} = \beta_k > 0$ and $\sigma_{ijuv,k} = \sigma_k > 0$, for all $i, j, u, v$. Then

$$P_{k|k} \leq \alpha_k \left(1 + n_u \beta_k^{-1}\right) (I - K_k m)(I - K_k m)^T + \beta_k + n_v \sigma_k K_k \left(\sum_{i=1}^{n_u} \sum_{j=1}^{n_v} T_{ij} \right) K_k^T + \gamma K_kK_k^T,$$

(3)

where $n_0$ is the number of non null radius of $[C]$. The right term of (3) is denoted by $P_{k|k}$. The optimal gain $K_k$ which minimizes the trace of $P_{k|k}$ is

$$K_k^* = m^T \left(\frac{mn^T + u_kD + v_kI}{n_0}\right)^{-1}$$

where

$$D = \sum_{i=1}^{n_u} \sum_{j=1}^{n_v} T_{ij} r_{ij} r_{ij}^T, \quad u_k = \frac{\beta_k + n_v \sigma_k}{1 + n_0 \beta_k}, \quad v_k = \frac{\alpha_k}{1 + n_0 \beta_k}.$$ By choosing $K_k = K_k^*$ we get

$$P_{k|k} = \alpha_k \left(1 + n_u \beta_k^{-1}\right) (I - K_k m).$$

The trace of $P_{k|k}$ is optimal according to the choice $K_k = K_k^*$, but we can do better by well choosing the coefficients $\beta_k$ and $\sigma_k$. We have

$$\text{tr}(P_{k|k}) = \alpha_k \left(1 + n_u \beta_k^{-1}\right) \text{tr} \left[I - m^T \left(\frac{mn^T + u_kD + v_kI}{n_0}\right)^{-1} m\right] = \alpha_k \left(1 + n_u \beta_k^{-1}\right) \left[\text{tr}(I) - \text{tr} \left(\frac{mn^T + u_kD + v_kI}{n_0}\right) \right] = \alpha_k \left(\beta_k + n_v \sigma_k\right) \text{tr} \left(D \left(\frac{mn^T + u_kD + v_kI}{n_0}\right) \right) + \gamma \text{tr} \left(\frac{mn^T + u_kD + v_kI}{n_0}\right)$$

We observe that if $\beta_k$ and $\sigma_k$ converge to 0, then $\text{tr}(P_{k|k})$ converges to $\gamma \text{tr} \left(\frac{mn^T}{n_0}\right)$. The use of upper bounds of $P_{k|k-1}$ and $[R]$ with the forms $\alpha I$ ($\alpha > 0$) decreases
the computation time of the algorithm (with a rate more than 40% according to a numerical result). In addition, by choosing $\beta_k$ and $\sigma_k$ sufficient small, we can control the trace of $P_{k|k}$.

IV. NUMERICAL EXAMPLE

We simulate an example described by equation (1) with no input, where:

$$
\begin{bmatrix}
A &=& \begin{bmatrix} 2.45 & 2.72 \\ 6.32 & 6.98 \\ -0.79 & -0.72 \end{bmatrix}, \\
C &=& \begin{bmatrix} -8.16 & -7.84 \\ -2.04 & -1.96 \\ -0.41 & -0.39 \end{bmatrix}, \\
Q &=& \begin{bmatrix} 8.12 & -6 & 4 \\ -6 & 8.12 & 1.6 & 2.4 \\ 3.2 & 4.8 & 1.6 & 2.4 & 8 & 12 \end{bmatrix}.
\end{bmatrix}
$$

The initial state is $x_0 = (5, -2, 6)^T$ and the model starts at $\hat{x}_0 = (\{[-2,2], [-2,2], [-2,2]\})^T$. The initial error covariance bound is $P_{0|0} = 10I$.

First, we simulate with $N = 10000$ steps for state variables $x_k$, measures $y_k$ and covariance matrices $P_{k|k}$. More precisely, at each step $k$, from $[A], [C], [Q], [R]$, we generate respectively matrices $A_k, C_k, Q_k, R_k$ such that $Q_k$ and $R_k$ are symmetric positive semi-definite. Then $w_k, v_k$ are simulated such that $w_k \sim \mathcal{N}(0, Q_k)$ and $v_k \sim \mathcal{N}(0, R_k)$. From these informations, we can calculate $x_k, y_k$ and $P_{k|k}$.

In a second phase, we run our algorithms, named OUBIKF (Optimal Upper Bound Interval Kalman Filter), together with the one of [7], named UBIKF, for $N$ steps to obtain $\hat{x}_k^{\text{opt}}$, $P_{k|k}^{\text{opt}}$ and $\hat{x}_k$, $P_{k|k}$ respectively. The following results are adapted to the choice of upper bounds $\alpha l$ with $\alpha = \|\text{Max}\|_F$ and of coefficients $\beta_k = \frac{1}{\sum_{n=0}^{10^3}}$ and $\sigma_k = \frac{1}{\sum_{n=0}^{10^3}}$.

Simulations results

The computation time of OUBIKF is reduced more than 40% w.r.t the one of UBIKF (see Table I).

<table>
<thead>
<tr>
<th>RMSE</th>
<th>Time</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>$x_1$</td>
</tr>
<tr>
<td>UBIKF</td>
<td>413.41</td>
</tr>
<tr>
<td>OUBIKF</td>
<td>416.95</td>
</tr>
</tbody>
</table>

TABLE I: Results of the OUBIKF versus UBIKF

The traces of bounds $P_{k|k}^{\text{opt}}$ decrease rapidly and have a convergence tendency while the traces of $P_{k|k}$ increase (although bounded) (Fig. 1, Fig. 2).

In addition, we have $\text{tr}(P_{k|k}) \leq \text{tr}(P_{k|k}^{\text{opt}}) \leq \text{tr}(P_{k|k})$ for all $k \geq 1$. This fact is verified experimentally for all $k \geq 1$ and a summary is presented in Table II. Furthermore, all estimate intervals $[\hat{x}_k]^{\text{opt}}$ are contained in the corresponding estimate intervals $[\hat{x}_k]$.

The next result concerns the confidence intervals defined by

$$
\begin{bmatrix}
\text{Cl}_{k,i}^{\text{opt}} &=& \left\{\left.\inf(\{[\hat{x}_{k,i}]^{\text{opt}}\}) - r \sqrt{P_{k,ii}}\right|,\sup(\{[\hat{x}_{k,i}]^{\text{opt}}\}) + r \sqrt{P_{k,ii}}\right\}, \\
\text{Cl}_{k,i} &=& \left\{\left.\inf(\{[\hat{x}_{k,i}]\}) - r \sqrt{P_{k,ii}}\right|,\sup(\{[\hat{x}_{k,i}]\}) + r \sqrt{P_{k,ii}}\right\}
\end{bmatrix}
$$

for $i = 1, \ldots, n_x$ and $r = 1, 2, 3$ corresponding to 68%, 95%, 99.7% confidence interval (the 3-sigma rule). According to the simulation, the 68% confidence intervals contain all corresponding state variables $x_k$ and, more over, $\text{Cl}_{k,i}^{\text{opt}} \subseteq \text{Cl}_{k,i}, \forall k \geq 1, \forall i = 1, \ldots, 3$ (Fig. 3).

So the $O(\%)$ which is the percentage of confidence intervals containing corresponding state variables are both 100% for two algorithms, however the $\text{Cl}_{k,i}^{\text{opt}}$’s are more consistent.

We note that the 68% confidence intervals do not always contain the corresponding state variables with $O(\%) = 100\%$ for different simulations (with the same input), but often reach over 99.9%. And until now, none of our simulations for
Concerning the meaning of the confidence interval definition presented above, we can think in the manner that \( \text{CI}_{k,i} = \bigcup_{\hat{x}_{k,i} \in [\hat{x}_{k,i}]} \text{CI}_{k,i}(\hat{x}_{k,i}) \) where \( \text{CI}_{k,i}(\hat{x}_{k,i}) = [\hat{x}_{k,i} - r\sqrt{P_{k,i}}, \hat{x}_{k,i} + r\sqrt{P_{k,i}}] \). A state \( x_k \) belonging to \( \text{CI}_{k,i} \) means that \( x_k \in \text{CI}_{k,i}(\hat{x}_{k,i}) \) for some \( \hat{x}_{k,i} \in [\hat{x}_{k,i}] \). It is the same thing for \( \text{CI}^{opt}_{k,i} \).

We also deal with a criterion called Root Mean Squared Error (RMSE) to compare the performance of the two algorithms. The RMSE is defined by

\[
\text{RMSE}_i = \sqrt{\frac{1}{N} \sum_{k=1}^{N} (x_{k,i} - \text{mid}([\hat{x}_{k,i}]))^2}
\]

for \( i = 1, \ldots, n_x \). And the result is that the RMSE for OUBIKF is slightly increasing w.r.t the one for UBIKIF (Table I). We use this criterion since it has been used before to compare different algorithms, e.g. in [7]. But a critical point of view can be pointed out. The distance between the state \( x_{k,i} \) and the center point of the corresponding estimate interval is used. This fact dismisses the issue of the estimate interval width. Naturally, two estimate intervals with the same center point have the same RMSE. In other words, this index just stand for the concentration of state \( x_k \) with respect to the corresponding estimate interval center point. We propose another distance to improve the meaning of this criterion. We will use the Hausdorff distance defined as follow:

\[
d_H(X,Y) = \max \left\{ \sup_{x \in X} \inf_{y \in Y} d(x,y), \sup_{y \in Y} \inf_{x \in X} d(x,y) \right\}
\]

for any two non empty sets \( X, Y \) in the metric space \((\Omega, d)\). In our case, we have

\[
d_H(x_{k,i}, [\hat{x}_{k,i}]) = \max \{ |x_{k,i} - \inf([\hat{x}_{k,i}])|, |x_{k,i} - \sup([\hat{x}_{k,i}])| \}
\]

and the new RMSE is defined by

\[
\hat{\text{RMSE}}_i = \sqrt{\frac{1}{N} \sum_{k=1}^{N} d_H(x_{k,i}, [\hat{x}_{k,i}])^2}
\]

The result for \( \hat{\text{RMSE}} \) in Table III shows that the estimate intervals \( [x^{opt}_{k,i}] \) are more relevant by their tightness.

**TABLE II: Traces of Covariance matrices and Traces of its Upper bounds**

<table>
<thead>
<tr>
<th></th>
<th>( x_1 )</th>
<th>( x_2 )</th>
<th>( x_3 )</th>
</tr>
</thead>
<tbody>
<tr>
<td>UBIKF</td>
<td>5047.2</td>
<td>4159.1</td>
<td>4213.6</td>
</tr>
<tr>
<td>OUBIKF</td>
<td>4708.5</td>
<td>3847.7</td>
<td>3934.2</td>
</tr>
</tbody>
</table>

**V. Conclusion**

This paper proposes a novel result to find an optimal upper bound of set \( S_{\frac{1}{2}}([M]) \) that ensures a solution to the singularity problem of the interval matrix inversion as well as the conservativeness of the algorithms. Based on that result, an Optimal Upper Bound Interval Kalman Filter (OUBIKF) is developed to perform an optimal state estimation that encloses the set of all possible solutions w.r.t admissible uncertainties. Simulations results shows the efficiency and accuracy of the proposed strategy.

**References**