

# Package: FKF (via r-universe)

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**Title** Fast Kalman Filter

**Version** 0.2.6

**Description** This is a fast and flexible implementation of the Kalman filter and smoother, which can deal with NAs. It is entirely written in C and relies fully on linear algebra subroutines contained in BLAS and LAPACK. Due to the speed of the filter, the fitting of high-dimensional linear state space models to large datasets becomes possible. This package also contains a plot function for the visualization of the state vector and graphical diagnostics of the residuals.

**License** GPL (>= 2)

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fkf	<i>Fast Kalman filter</i>
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### Description

This function allows for fast and flexible Kalman filtering. Both, the measurement and transition equation may be multivariate and parameters are allowed to be time-varying. In addition “NA”-values in the observations are supported. `fkf` wraps the C-function `FKF` which fully relies on linear algebra subroutines contained in `BLAS` and `LAPACK`.

### Usage

```
fkf(a0, P0, dt, ct, Tt, Zt, HHt, GGt, yt)
```

### Arguments

<code>a0</code>	A vector giving the initial value/estimation of the state variable.
<code>P0</code>	A matrix giving the variance of <code>a0</code> .
<code>dt</code>	A matrix giving the intercept of the transition equation (see <b>Details</b> ).
<code>ct</code>	A matrix giving the intercept of the measurement equation (see <b>Details</b> ).
<code>Tt</code>	An array giving the factor of the transition equation (see <b>Details</b> ).
<code>Zt</code>	An array giving the factor of the measurement equation (see <b>Details</b> ).
<code>HHt</code>	An array giving the variance of the innovations of the transition equation (see <b>Details</b> ).
<code>GGt</code>	An array giving the variance of the disturbances of the measurement equation (see <b>Details</b> ).
<code>yt</code>	A matrix containing the observations. “NA”-values are allowed (see <b>Details</b> ).

### Details

#### State space form

The following notation is closest to the one of Koopman et al. The state space model is represented by the transition equation and the measurement equation. Let  $m$  be the dimension of the state variable,  $d$  be the dimension of the observations, and  $n$  the number of observations. The transition equation and the measurement equation are given by

$$\alpha_{t+1} = d_t + T_t \cdot \alpha_t + H_t \cdot \eta_t$$

$$y_t = c_t + Z_t \cdot \alpha_t + G_t \cdot \epsilon_t,$$

where  $\eta_t$  and  $\epsilon_t$  are iid  $N(0, I_m)$  and iid  $N(0, I_d)$ , respectively, and  $\alpha_t$  denotes the state variable. The parameters admit the following dimensions:

$$\begin{array}{lll} \alpha_t \in R^m & d_t \in R^m & \eta_t \in R^m \\ T_t \in R^{m \times m} & H_t \in R^{m \times m} & \\ y_t \in R^d & c_t \in R^d & \epsilon_t \in R^d \\ Z_t \in R^{d \times m} & G_t \in R^{d \times d} & \end{array}$$

Note that fkf takes as input HHT and GGt which corresponds to  $H_t H_t'$  and  $G_t G_t'$ .

### Iteration:

The filter iterations are implemented using the expected values

$$a_t = E[\alpha_t | y_1, \dots, y_{t-1}]$$

$$a_{t|t} = E[\alpha_t | y_1, \dots, y_t]$$

and variances

$$P_t = Var[\alpha_t | y_1, \dots, y_{t-1}]$$

$$P_{t|t} = Var[\alpha_t | y_1, \dots, y_t]$$

of the state  $\alpha_t$  in the following way (for the case of no NA's):

Initialisation: Set  $t = 1$  with  $a_t = a_0$  and  $P_t = P_0$

Updating equations:

$$v_t = y_t - c_t - Z_t a_t$$

$$F_t = Z_t P_t Z_t' + G_t G_t'$$

$$K_t = P_t Z_t' F_t^{-1}$$

$$a_{t|t} = a_t + K_t v_t$$

$$P_{t|t} = P_t - P_t Z_t' K_t'$$

Prediction equations:

$$a_{t+1} = d_t + T_t a_{t|t}$$

$$P_{t+1} = T_t P_{t|t} T_t' + H_t H_t'$$

Next iteration: Set  $t = t + 1$  and goto "Updating equations".

### NA-values:

NA-values in the observation matrix  $y_t$  are supported. If particular observations  $y_t[i]$  contain NAs, the NA-values are removed and the measurement equation is adjusted accordingly. When the full vector  $y_t[i]$  is missing the Kalman filter reduces to a prediction step.

### Parameters:

The parameters can either be constant or deterministic time-varying. Assume the number of observations is  $n$  (i.e.  $y = (y_t)_{t=1, \dots, n}$ ,  $y_t = (y_{t1}, \dots, y_{td})$ ). Then, the parameters admit the following classes and dimensions:

dt either a  $m \times n$  (time-varying) or a  $m \times 1$  (constant) matrix.  
 Tt either a  $m \times m \times n$  or a  $m \times m \times 1$  array.  
 HHT either a  $m \times m \times n$  or a  $m \times m \times 1$  array.  
 ct either a  $d \times n$  or a  $d \times 1$  matrix.  
 Zt either a  $d \times m \times n$  or a  $d \times m \times 1$  array.  
 GGt either a  $d \times d \times n$  or a  $d \times d \times 1$  array.  
 yt a  $d \times n$  matrix.

### BLAS and LAPACK routines used:

The R function `fkf` basically wraps the C-function `FKF`, which entirely relies on linear algebra subroutines provided by BLAS and LAPACK. The following functions are used:

BLAS: `dcopy`, `dgemm`, `daxpy`.  
 LAPACK: `dpotri`, `dpotrf`.

`FKF` is called through the `.Call` interface. Internally, `FKF` extracts the dimensions, allocates memory, and initializes the R-objects to be returned. `FKF` subsequently calls `cfkf` which performs the Kalman filtering.

The only critical part is to compute the inverse of  $F_t$  and the determinant of  $F_t$ . If the inverse can not be computed, the filter stops and returns the corresponding message in `status` (see **Value**). If the computation of the determinant fails, the filter will continue, but the log-likelihood (element `logLik`) will be “NA”.

The inverse is computed in two steps: First, the Cholesky factorization of  $F_t$  is calculated by `dpotrf`. Second, `dpotri` calculates the inverse based on the output of `dpotrf`.

The determinant of  $F_t$  is computed using again the Cholesky decomposition.

The first element of both `at` and `Pt` is filled with the function arguments `a0` and `P0`, and the last, i.e. the  $(n + 1)$ -th, element of `at` and `Pt` contains the predictions for the next time step.

### Value

An S3-object of class “`fkf`”, which is a list with the following elements:

`att` A  $m \times n$ -matrix containing the filtered state variables, i.e.  $att[,t] = a_{t|t}$ .  
`at` A  $m \times (n + 1)$ -matrix containing the predicted state variables, i.e.  $at[,t] = a_t$ .  
`Ptt` A  $m \times m \times n$ -array containing the variance of `att`, i.e.  $Ptt[:,t] = P_{t|t}$ .  
`Pt` A  $m \times m \times (n + 1)$ -array containing the variances of `at`, i.e.  $Pt[:,t] = P_t$ .  
`vt` A  $d \times n$ -matrix of the prediction errors i.e.  $vt[,t] = v_t$ .  
`Ft` A  $d \times d \times n$ -array which contains the variances of `vt`, i.e.  $Ft[:,t] = F_t$ .  
`Kt` A  $m \times d \times n$ -array containing the “Kalman gain” i.e.  $Kt[:,t] = k_t$ .  
`logLik` The log-likelihood.  
`status` A vector which contains the status of LAPACK’s `dpotri` and `dpotrf`. (0, 0) means successful exit.  
`sys.time` The time elapsed as an object of class “`proc_time`”.

### References

Harvey, Andrew C. (1990). *Forecasting, Structural Time Series Models and the Kalman Filter*. Cambridge University Press.

Hamilton, James D. (1994). *Time Series Analysis*. Princeton University Press.

Koopman, S. J., Shephard, N., Doornik, J. A. (1999). *Statistical algorithms for models in state space using SsfPack 2.2*. *Econometrics Journal*, Royal Economic Society, vol. 2(1), pages 107-160.

### See Also

`plot` to visualize and analyze `fkf`-objects, `KalmanRun` from the `stats` package, function `dlmFilter` from package `dlm`.

### Examples

```
## ----->
## Example: Local level model for the Nile's annual flow.
## ----->
## Transition equation:
## alpha[t+1] = alpha[t] + eta[t], eta[t] ~ N(0, HHT)
## Measurement equation:
## y[t] = alpha[t] + eps[t], eps[t] ~ N(0, GGt)

y <- Nile
y[c(3, 10)] <- NA # NA values can be handled

## Set constant parameters:
dt <- ct <- matrix(0)
Zt <- Tt <- matrix(1)
a0 <- y[1] # Estimation of the first year flow
P0 <- matrix(100) # Variance of 'a0'

## Estimate parameters:
fit.fkf <- optim(c(HHT = var(y, na.rm = TRUE) * .5,
                 GGt = var(y, na.rm = TRUE) * .5),
               fn = function(par, ...)
                 -fkf(HHT = matrix(par[1]), GGt = matrix(par[2]), ...) $logLik,
                 yt = rbind(y), a0 = a0, P0 = P0, dt = dt, ct = ct,
                 Zt = Zt, Tt = Tt)

## Filter Nile data with estimated parameters:
fkf.obj <- fkf(a0, P0, dt, ct, Tt, Zt, HHT = matrix(fit.fkf$par[1]),
              GGt = matrix(fit.fkf$par[2]), yt = rbind(y))

## Compare with the stats' structural time series implementation:
fit.stats <- StructTS(y, type = "level")

fit.fkf$par
fit.stats$coef

## Plot the flow data together with fitted local levels:
plot(y, main = "Nile flow")
lines(fitted(fit.stats), col = "green")
lines(ts(fkf.obj$att[1, ], start = start(y), frequency = frequency(y)), col = "blue")
legend("top", c("Nile flow data", "Local level (StructTS)", "Local level (fkf)"),
      col = c("black", "green", "blue"), lty = 1)
```

fks

*Fast Kalman Smoother***Description**

This function can be run after running `fkf` to produce "smoothed" estimates of the state variable  $\alpha_t$ . Unlike the output of the filter, these estimates are conditional on the entire set of  $n$  data points rather than only the past, see details.

**Usage**

```
fks(FKFobj)
```

**Arguments**

FKFobj            An S3-object of class "fkf", returned by `fkf`.

**Details**

The following notation is taken from the `fkf` function descriptions and is close to the one of Koopman et al. The smoother estimates

$$a_{t|n} = E[\alpha_t | y_1, \dots, y_n]$$

$$P_{t|n} = Var[\alpha_t | y_1, \dots, y_n]$$

based on the outputs of the forward filtering pass performed by `fkf`.

The formulation of Koopman and Durbin is used which evolves the two values  $r_t \in R^m$  and  $N_t \in R^{m \times m}$  to avoid inverting the covariance matrix.

**Iteration:**

If there are no missing values the iteration proceeds as follows:

Initialisation: Set  $t = n$ , with  $r_t = 0$  and  $N_t = 0$ .

Evolution equations:

$$L = T_t - T_t K_t Z_t$$

$$r_{t-1} = Z_t' F_t^{-1} v_t + L' r_t$$

$$N_{t-1} = Z_t' F_t^{-1} Z_t + L' N_t L$$

Updating equations:

$$a_{t|n} = a_{t|t-1} + P_{t|t-1} r_{t-1}$$

$$P_{t|n} = P_{t|t-1} - P_{t|t-1} N_{t-1} P_{t|t-1}$$

Next iteration: Set  $t = t - 1$  and goto "Evolution equations".

**Value**

An S3-object of class "fks" which is a list with the following elements:

ahatt A  $m \times n$ -matrix containing the smoothed state variables, i.e.  $\text{ahatt}[t] = a_{t|n}$

Vt A  $m \times m \times n$ -array containing the variances of ahatt, i.e.  $\text{Vt}[t] = P_{t|n}$

**References**

Koopman, S. J. and Durbin, J. (2000). *Fast filtering and smoothing for multivariate state space models* Journal of Time Series Analysis Vol. 21, No. 3

**Examples**

```
## ----->
## Example: Local level model for the Nile's annual flow.
## ----->
## Transition equation:
## alpha[t+1] = alpha[t] + eta[t], eta[t] ~ N(0, HHT)
## Measurement equation:
## y[t] = alpha[t] + eps[t], eps[t] ~ N(0, GGt)

y <- Nile
y[c(3, 10)] <- NA # NA values can be handled

## Set constant parameters:
dt <- ct <- matrix(0)
Zt <- Tt <- matrix(1)
a0 <- y[1] # Estimation of the first year flow
P0 <- matrix(100) # Variance of 'a0'

## Estimate parameters:
fit.fkf <- optim(c(HHT = var(y, na.rm = TRUE) * .5,
                 GGt = var(y, na.rm = TRUE) * .5),
               fn = function(par, ...)
                 -fkf(HHT = matrix(par[1]), GGt = matrix(par[2]), ...) $logLik,
                 yt = rbind(y), a0 = a0, P0 = P0, dt = dt, ct = ct,
                 Zt = Zt, Tt = Tt)

## Filter Nile data with estimated parameters:
fkf.obj <- fkf(a0, P0, dt, ct, Tt, Zt, HHT = matrix(fit.fkf$par[1]),
              GGt = matrix(fit.fkf$par[2]), yt = rbind(y))

## Smooth the data based on the filter object
fks.obj <- fks(fkf.obj)

## Plot the flow data together with local levels:
plot(y, main = "Nile flow")
lines(ts(fkf.obj$att[1, ], start = start(y), frequency = frequency(y)), col = "blue")
lines(ts(fks.obj$ahatt[1, ], start = start(y), frequency = frequency(y)), col = "red")
legend("top", c("Nile flow data", "Local level (fkf)", "Local level (fks)"),
      col = c("black", "green", "blue", "red"), lty = 1)
```

plot.fkf

Plotting *fkf* objects**Description**

Plotting method for objects of class `fkf`. This function provides tools for graphical analysis of the Kalman filter output: Visualization of the state vector, QQ-plot of the individual residuals, QQ-plot of the Mahalanobis distance, auto- as well as crosscorrelation function of the residuals.

**Usage**

```
## S3 method for class 'fkf'
plot(
  x,
  type = c("state", "resid.qq", "qqchisq", "acf"),
  CI = 0.95,
  at.idx = 1:nrow(x$at),
  att.idx = 1:nrow(x$att),
  ...
)
```

**Arguments**

<code>x</code>	The output of <code>fkf</code> .
<code>type</code>	A string stating what shall be plotted (see <b>Details</b> ).
<code>CI</code>	The confidence interval in case <code>type == "state"</code> . Set <code>CI</code> to <code>NA</code> if no confidence interval shall be plotted.
<code>at.idx</code>	An vector giving the indexes of the predicted state variables which shall be plotted if <code>type == "state"</code> .
<code>att.idx</code>	An vector giving the indexes of the filtered state variables which shall be plotted if <code>type == "state"</code> .
<code>...</code>	Arguments passed to either <code>plot</code> , <code>qqnorm</code> , <code>qqplot</code> or <code>acf</code> .

**Details**

The argument `type` states what shall be plotted. `type` must partially match one of the following:

`state` The state variables are plotted. By the arguments `at.idx` and `att.idx`, the user can specify which of the predicted ( $a_t$ ) and filtered ( $a_{t|t}$ ) state variables will be drawn.

`resid.qq` Draws a QQ-plot for each residual-series `inv`.

`qqchisq` A Chi-Squared QQ-plot will be drawn to graphically test for multivariate normality of the residuals based on the Mahalanobis distance.

`acf` Creates a pairs plot with the autocorrelation function (`acf`) on the diagonal panels and the crosscorrelation function (`ccf`) of the residuals on the off-diagonal panels.

**Value**

Invisibly returns an list with components:

`distance` The Mahalanobis distance of the residuals as a vector of length  $n$ .  
`std.resid` The standardized residuals as an  $d \times n$ -matrix. It should hold that  $std.resid_{ij} iid \sim N_d(0, I)$ ,

where  $d$  denotes the dimension of the data and  $n$  the number of observations.

**usage**

```
plot(x, type = c("state", "resid.qq", "qqchisq", "acf"), CI = 0.95, at.idx = 1:nrow(x$at),
att.idx = 1:nrow(x$att), ...)
```

**See Also**

[fkf](#)

**Examples**

```
## ----->
## Example: Local level model for the treering data
## ----->
## Transition equation:
## alpha[t+1] = alpha[t] + eta[t], eta[t] ~ N(0, HHT)
## Measurement equation:
## y[t] = alpha[t] + eps[t], eps[t] ~ N(0, GGt)

y <- treering
y[c(3, 10)] <- NA # NA values can be handled

## Set constant parameters:
dt <- ct <- matrix(0)
Zt <- Tt <- array(1,c(1,1,1))
a0 <- y[1] # Estimation of the first width
P0 <- matrix(100) # Variance of 'a0'

## Estimate parameters:
fit.fkf <- optim(c(HHT = var(y, na.rm = TRUE) * .5,
                 GGt = var(y, na.rm = TRUE) * .5),
               fn = function(par, ...)
                 -fkf(HHT = array(par[1],c(1,1,1)), GGt = array(par[2],c(1,1,1)), ...) $logLik,
                 yt = rbind(y), a0 = a0, P0 = P0, dt = dt, ct = ct,
                 Zt = Zt, Tt = Tt)

## Filter tree ring data with estimated parameters:
fkf.obj <- fkf(a0, P0, dt, ct, Tt, Zt, HHT = array(fit.fkf$par[1],c(1,1,1)),
              GGt = array(fit.fkf$par[2],c(1,1,1)), yt = rbind(y))

## Plot the width together with fitted local levels:
plot(y, main = "Treering data")
lines(ts(fkf.obj$att[1, ], start = start(y), frequency = frequency(y)), col = "blue")
```

```

legend("top", c("Treering data", "Local level"), col = c("black", "blue"), lty = 1)

## Check the residuals for normality:
plot(fkf.obj, type = "resid.qq")

## Test for autocorrelation:
plot(fkf.obj, type = "acf", na.action = na.pass)

```

---

plot.fks

*Plotting fks objects*


---

## Description

Plotting method for objects of class `fks`. This function provides tools visualisation of the state vector of the Kalman smoother output

## Usage

```

## S3 method for class 'fks'
plot(x, CI = 0.95, ahatt.idx = 1:nrow(x$ahatt), ...)

```

## Arguments

<code>x</code>	The output of <code>fks</code> .
<code>CI</code>	The confidence interval in case <code>type == "state"</code> . Set <code>CI</code> to <code>NA</code> if no confidence interval shall be plotted.
<code>ahatt.idx</code>	An vector giving the indexes of the predicted state variables which shall be plotted if <code>type == "state"</code> .
<code>...</code>	Arguments passed to either <code>plot</code> , <code>qqnorm</code> , <code>qqplot</code> or <code>acf</code> .

## Details

The state variables are plotted. By the argument `ahatt.idx`, the user can specify which of the smoothed ( $a_{t|n}$ ) state variables will be drawn.

## See Also

`fks`

## Examples

```

## <----->
## Example 3: Local level model for the treering data
## <----->
## Transition equation:
## alpha[t+1] = alpha[t] + eta[t], eta[t] ~ N(0, HHT)
## Measurement equation:

```

```
## y[t] = alpha[t] + eps[t], eps[t] ~ N(0, GGt)

y <- treering
y[c(3, 10)] <- NA # NA values can be handled

## Set constant parameters:
dt <- ct <- matrix(0)
Zt <- Tt <- array(1,c(1,1,1))
a0 <- y[1] # Estimation of the first width
P0 <- matrix(100) # Variance of 'a0'

## Estimate parameters:
fit.fkf <- optim(c(HHt = var(y, na.rm = TRUE) * .5,
                 GGt = var(y, na.rm = TRUE) * .5),
               fn = function(par, ...)
                 -fkf(HHt = array(par[1],c(1,1,1)), GGt = array(par[2],c(1,1,1)), ...) $logLik,
                 yt = rbind(y), a0 = a0, P0 = P0, dt = dt, ct = ct,
                 Zt = Zt, Tt = Tt)

## Filter tree ring data with estimated parameters:
fkf.obj <- fkf(a0, P0, dt, ct, Tt, Zt, HHt = array(fit.fkf$par[1],c(1,1,1)),
              GGt = array(fit.fkf$par[2],c(1,1,1)), yt = rbind(y))

fks.obj <- fks(fkf.obj)
plot(fks.obj)
##lines(as.numeric(y),col="blue")
```

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