

Markov chain

- A **Markov chain** is a special sort of belief network:



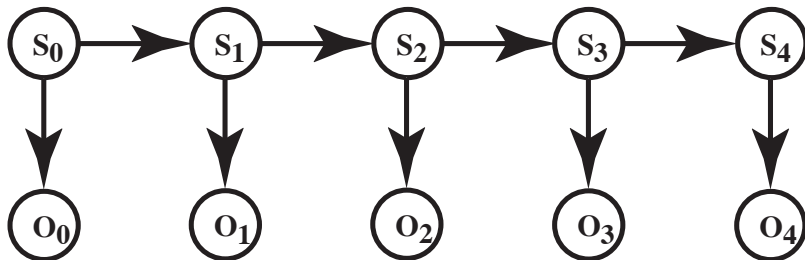
- Thus $P(S_{t+1}|S_0, \dots, S_t) = P(S_{t+1}|S_t)$.
- Often S_t represents the **state** at time t . Intuitively S_t conveys all of the information about the history that can affect the future states.
- “The past is independent of the future given the present.”

Stationary Markov chain

- A **stationary Markov chain** is when for all $t > 0$, $t' > 0$,
 $P(S_{t+1}|S_t) = P(S_{t'+1}|S_{t'})$.
- We specify $P(S_0)$ and $P(S_{t+1}|S_t)$.
 - ▶ Simple model, easy to specify
 - ▶ Often the natural model
 - ▶ The network can extend indefinitely

Hidden Markov Model

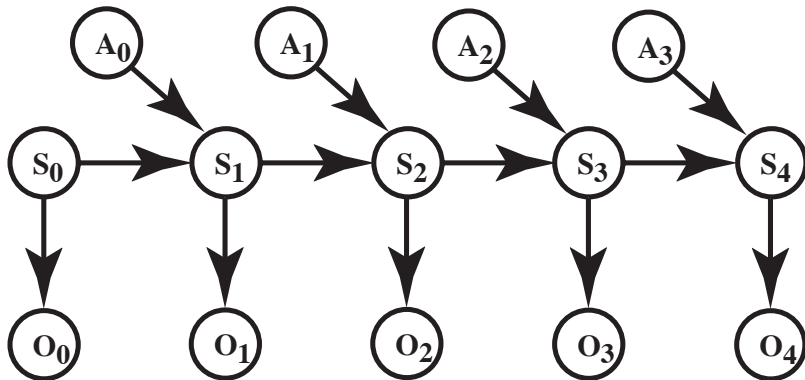
- A **Hidden Markov Model (HMM)** is a belief network:



- $P(S_0)$ specifies initial conditions
- $P(S_{t+1}|S_t)$ specifies the dynamics
- $P(O_t|S_t)$ specifies the sensor model

Example: localization

- Suppose a robot wants to determine its location based on its actions and its sensor readings: **Localization**
- This can be represented by the augmented HMM:



Example localization domain

- Circular corridor, with 16 locations:



- Doors at positions: 2, 4, 7, 11.
- Noisy Sensors
- Stochastic Dynamics
- Robot starts at an unknown location and must determine where it is.

Example Sensor Model

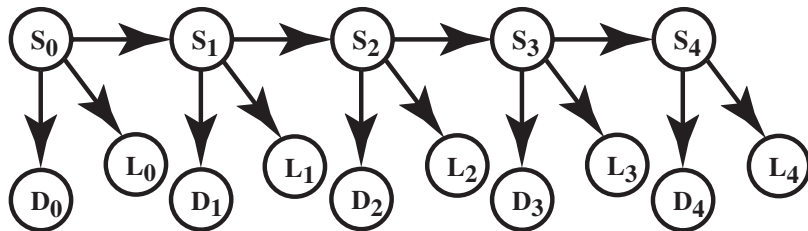
- $P(\text{Observe Door} \mid \text{At Door}) = 0.8$
- $P(\text{Observe Door} \mid \text{Not At Door}) = 0.1$

Example Dynamics Model

- $P(\text{loc}_{t+1} = L | \text{action}_t = \text{goRight} \wedge \text{loc}_t = L) = 0.1$
- $P(\text{loc}_{t+1} = L + 1 | \text{action}_t = \text{goRight} \wedge \text{loc}_t = L) = 0.8$
- $P(\text{loc}_{t+1} = L + 2 | \text{action}_t = \text{goRight} \wedge \text{loc}_t = L) = 0.074$
- $P(\text{loc}_{t+1} = L' | \text{action}_t = \text{goRight} \wedge \text{loc}_t = L) = 0.002$ for any other location L' .
 - ▶ All location arithmetic is modulo 16.
 - ▶ The action *goLeft* works the same but to the left.

Combining sensor information

- **Example:** we can combine information from a light sensor and the door sensor **Sensor Fusion**



S_t robot location at time t

D_t door sensor value at time t

L_t light sensor value at time t