

LiMa: Sequential Lifted Marginal Filtering on Multiset State Descriptions





- Providing automated assistance for people suffering from dementia requires the system to reason about the current situation from noisy and ambiguous sensor data
- Typical **non-obtrusive sensors** to measure the system state include accelerometers or smart home systems
- These sensor information are used to estimate the current situation in order to answer application specific questions, e.g. "Where is Alice?" or "What is Alice holding?"





Alice, Bob & Charlie scenario



• Alice, Bob & Charlie can move between all locations after entering through the door • **Observations** indicate the presence of at least one of them at a location. A sample sequence is shown on the right (black indicates presence, gray absence). • They can print a document if paper is provided and get a coffee if ground coffee and water is provided as well as **replenish** any of these resources • Their goal is to get a coffee and to print a document



- Abstract from **particular states** that represent instances of the same group of undistinguishable situations in order to represent and consider them during inference together
- Abstraction is done by separating the structure of the state from the particular value distributions that may be inserted into that structure
- In order to represent uncertainty about the situation, we use a probability distribution over this abstract state representation



- During the inference, there sometimes are **identifying observations** that enable to introduce evidence about some entities
- Identifying sensors are e.g. ID-card sensors or personal devices,

Problem Statement

• For an increasing number of entities, grounded inference leads to a **combinatorial** explosion in the number of hypotheses that need to be considered (i.e. the number of states to be tracked simul-



Non-identifying sensors are e.g. presence sensors or light switches



- Splits increase the number of hypotheses that need to be tracked



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