Final Exam SCE2202
System identification and optimal estimation
Thursday June 6, 2013
Time: kl. 9.00 - 14.00

The final exam consists of: 5 tasks.
The exam counts 70% of the final grade.
Available aids: pen and paper
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Task 1 (15%): Diverse questions

a) Given a 1st order system (ie. a system with one state)

$$x_{k+1} = ax_k + bu_k + ke_k, \tag{1}$$
$$y_k = x_k + e_k, \tag{2}$$

where $k = a$ and a, b are unknown parameters and e_k is white noise.

Find a linear regression model of the form

$$y_k = \varphi_k^T \theta + e_k. \tag{3}$$

Define the parameter vector θ and the vector φ_k of regressors.

b) Given a relationship between temperature T and vapor pressure p, i.e.

$$p = e^{a - \frac{b}{T+c}}, \tag{4}$$

where a, b and c are constant parameters.

Find a linear regression model of the form

$$y_k = \varphi_k^T \theta + e_k. \tag{5}$$

Define the parameter vector θ and the vector φ_k of regressors.

c) Assume given t observations of a variable, say $y_k \ \forall \ k = 1, \ldots, t$. The mean after t observations is given by

$$\bar{y}_t = \frac{1}{t} \sum_{k=1}^{t} y_k. \tag{6}$$

Find a recursive formula for calculating the mean ?

d) Assume known impulse responses

$$H_k = DA^{k-1}B \ \forall \ k = 1, \cdots, 10. \tag{7}$$

Answer the following:

- Write up the Hankel matrices $\mathbf{H}_{1|L}$ and $\mathbf{H}_{2|L}$ where you should use $L = 2$.
- Show how you can find the system order, n, the extended observability matrix O_L and the extended controllability matrix C_J from a Singular Value decomposition (SVD) of $\mathbf{H}_{1|L}$.
- How are $\mathbf{H}_{1|L}$ and $\mathbf{H}_{2|L}$ related to O_L and C_J ?

Task 2 (15%): Ordinary Least Squares method and recursive system identification

a) Given a system

$$\begin{bmatrix} x_{k+1}^1 \\ x_{k+1}^2 \end{bmatrix} = \begin{bmatrix} -a_2 & 1 \\ -a_1 & 0 \end{bmatrix} \begin{bmatrix} x_k^1 \\ x_k^2 \end{bmatrix} + \begin{bmatrix} b_1 \\ b_2 \end{bmatrix} u_k + \begin{bmatrix} k_1 \\ k_2 \end{bmatrix} e_k \tag{8}$$

$$y_k = \begin{bmatrix} 1 & 0 \end{bmatrix} \begin{bmatrix} x_k^1 \\ x_k^2 \end{bmatrix} + e_k \tag{9}$$

For which values of the parameters k_1 and k_2 may the above model be written as an ARX model and hence as a linear regression model of the form

$$y_k = \varphi_k^T \theta_0 + e_k \tag{10}$$

- In particular, define the regression vector, φ_k, and the parameter vector, θ_0.
- Also define the parameters k_1 and k_2 such that the model, Eqs. (8) and (9), can be written as the linear regression model Eq. (10).
- Based on the regression model in Eq. (10) above, find a predictor, $\bar{y}_k(\theta)$, for the measurement y_k.
- Define the prediction error, ε_k.

b) Consider the following prediction error criterion

$$V_N(\theta) = \frac{1}{N} \sum_{k=1}^{N} \varepsilon_k^T \Lambda \varepsilon_k \tag{11}$$

where Λ is a specified and symmetric weighting matrix.

Find the Ordinary Least Squares (OLS) estimate, $\hat{\theta}_N$, of the true parameter vector θ_0.

c) Based on the OLS solution in step b) above, show how we can develop a recursive Ordinary Least Squares (ROLS) method of the following form

$$\hat{\theta}_t = \hat{\theta}_{t-1} + K_t (y_t - \varphi_t^T \hat{\theta}_{t-1}). \tag{12}$$

You shall in particular find equations for computing the gain, K_t, in Equation (12).

Task 3 (10%): The Kalman filter

a) Given a system modelled by a discrete time, state space model as follows

$$x_{k+1} = Ax_k + Bu_k + v_k, \tag{13}$$
$$y_k = Dx_k + Eu_k + w_k, \tag{14}$$

where v_k is white process noise and w_k is white measurements noise. Assume that the noise are uncorrelated, i.e. $\mathrm{E}(v_k w_k^T) = 0$.

- Write down a Kalman filter on apriori-aposteriori form for optimal estimation of the state vector x_k.
- Find a formula for the Kalman filter gain matrix, K, in the Kalman filter on apriori-aposteriori form.
- Show how the apriori-aposteriori formulation of the Kalman filter can be written as a Kalman filter on innovations form.
- Write down the Kalman-filter on prediction form for the system in Eqs. (13) and (14) ? Remark: The Kalman filter on prediction form is often used to calculate a prediction $\bar{y}_k$ of the output y_k and used in prediction error methods for system identification.

b) Given a non-linear system

$$x_{k+1} = f(x_k, u_k) + v_k, \tag{15}$$
$$y_k = g(x_k) + w_k, \tag{16}$$

where v_k and w_k are discrete white process noise and discrete white measurements noise, respectively.

Formulate the Kalman filter on apriori-aposteriori form for the non-linear system model in Eqs. (15) and (16).

Task 4 (15%): Subspace System Identification of Deterministic Systems: Using shift invariance principle

Consider the discrete time deterministic model, ie.

$$x_{k+1} = Ax_k + Bu_k, \tag{17}$$
$$y_k = Dx_k + Eu_k, \tag{18}$$

where the following output and input data matrices are known

$$Y = \begin{bmatrix} y_0^T \\ y_1^T \\ \vdots \\ y_{N-1}^T \end{bmatrix} \in \mathbb{R}^{N\times m}, \; U = \begin{bmatrix} u_0^T \\ u_1^T \\ \vdots \\ u_{N-1}^T \end{bmatrix} \in \mathbb{R}^{N\times r}. \tag{19}$$

a) Based on the model in Eqs. (17) and (18) and with known data as given in (19) we can develop the following matrix equation

$$Y_{0|L+1} = O_{L+1}X_0 + H_{L+1}^d U_{0|L+g}, \tag{20}$$

where $L \geq 1$ is a user specified positive integer parameter.

Write down the structure of the matrices in the matrix Eq. (20), with parameters $N = 12$, $L = 2$ and $g = 0$.

b) By using the known input-output data (19) and Eq. (20) we may formulate the projected equation

$$Z_{0|L+1} = O_{L+1}X_0^a \tag{21}$$

Find expressions for the data matrix $Z_{0|L+1}$.

Remark: define the projections which is involved in the expressions for $Z_{0|L+1}$.

c) Show how

- the system order, n
- the extended observability matrix O_{L+1}
- the system matrices A and D

can be estimated.

Task 5 (15%): Subspace System Identification: Combined Systems

Consider the discrete time model on innovations form, ie.

$$x_{k+1} = Ax_k + Bu_k + Ce_k, \tag{22}$$
$$y_k = Dx_k + Eu_k + Fe_k \tag{23}$$

where e_k is white noise with unit covariance matrix, i.e., $\mathrm{E}(e_k e_k^T) = I$ and where the following output and input data matrices are known

$$Y = \begin{bmatrix} y_0^T \\ y_1^T \\ \vdots \\ y_{N-1} \end{bmatrix} \in \mathbb{R}^{N\times m}, \; U = \begin{bmatrix} u_0^T \\ u_1^T \\ \vdots \\ u_{N-1} \end{bmatrix} \in \mathbb{R}^{N\times r}. \tag{24}$$

a) Based on the model in Eqs. (22) and (23) and with known data as given in (24) we can develop the following matrix equations

$$Y_{J|L} = O_L X_J + H_L^d U_{J|L+g-1} + H_L^s E_{J|L}, \tag{25}$$

$$Y_{J+1|L} = \tilde{A}_L Y_{J|L} + \tilde{B}_L U_{J|L+g} + \tilde{C}_L E_{J|L+1}, \tag{26}$$

where $J \geq 1$ and $L \geq 1$ are user specified positive integer numbers.

Write down the structure of the matrices in the matrix Eqs. (25) and (26), with parameters $N = 12$, $L = 2$, $J = 2$ and $g = 0$.

b) By using (24) and Eqs. (25) and (26) we may formulate the equations

$$Z_{J|L} = O_L X_J^a \tag{27}$$

and

$$Z_{J+1|L} = \tilde{A}_L Z_{J|L} \tag{28}$$

Find expressions for the data matrices $Z_{J|L}$ and $Z_{J+1|L}$ for the following case:

- a general combined deterministic and stochastic system.

Remark: define the projections $Z_{J+1|L}$ and $Z_{J|L}$.

c) Consider that the known input and output data as given in (24) are collected in closed loop, i.e., we assume that there is feedback in the known data.

From Eq. (23) with $E = 0$, or Eq. (25) with $L = 1$ and $g = 0$, we may define the matrix Equation

$$Y_{J|1} = D X_{J|1} + F E_{J|1} \tag{29}$$

- Define the data matrices $Y_{J|1}$, $X_{J|1}$ and $E_{J|1}$.

- When $J \rightarrow \infty$ we can prove that the following identity holds

$$X_{J|1} = X_{J|1} / \begin{bmatrix} U_{0|J} \\ Y_{0|J} \end{bmatrix} \tag{30}$$

Use (30) and (29) to find a projection

$$Z^s_{J|1} = FE_{J|1} \tag{31}$$

such that the innovations sequence

$$\begin{aligned} Z^s_{J|1} &= \begin{bmatrix} Fe_J & Fe_{J+1} & \dots & Fe_{N-1} \end{bmatrix} \\ &= \begin{bmatrix} \varepsilon_J & \varepsilon_{J+1} & \dots & \varepsilon_{N-1} \end{bmatrix} \end{aligned} \tag{32}$$

could be identified.

- Explain how this projection can be used in order to develop a subspace identification algorithm for closed loop systems.