

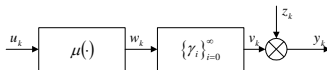
Hybrid Identification of L-N-L and N-L-N Systems

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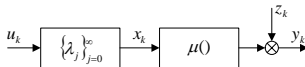
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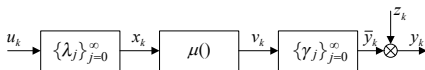
Block-oriented systems



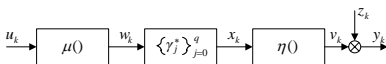
Hammerstein system (N-L)



Wiener system (L-N)



Wiener-Hammerstein system (L-N-L)



Hammerstein-Wiener system (N-L-N)

Parametric vs. nonparametric approach

Parametric

the system can be described with the use of
finite and known number of parameters

Non-parametric

the class of transformation is more general,
the number of necessary parameters is **infinite or unknown**

Examples of parametric models

nonlinear static block with polynomial characteristics

$$\mu(u) = \theta_p u^p + \theta_{p-1} u^{p-1} + \dots + \theta_1 u + \theta_0$$

p – known and finite

θ_i – unknown ($i = 0, 1, \dots, p$)

linear dynamics with ARMA difference equation

$$y_k = a_1 y_{k-1} + \dots + a_m y_{k-m} + b_0 u_k + \dots + b_n u_{k-n}$$

m, n – known and finite

a_i, b_j – unknown ($i = 1, 2, \dots, p, j = 0, 1, \dots, n$)

Typical assumptions in nonparametric approach

About nonlinearity

square integrable

Lipschitz

continuous

differentiable

invertible

About linear dynamics

asymptotically stable

invertible

About excitations

i.i.d. (normal/uniform distribution)

bounded

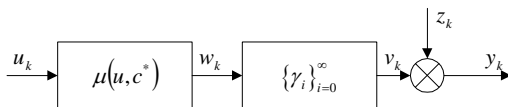
finite variance / finite 4th order moment

ergodicity

Identification methods

- **parametric**
 - least squares
 - instrumental variables
- **non-parametric**
 - kernel regression
 - orthogonal expansion

Two-stage identification of Hammerstein system



Hammerstein system

$$R(u) = \gamma_0 \mu(u) + \zeta$$

$$\hat{w}_k = \hat{R}(u_k) - \hat{R}(0)$$

$$\{(u_k, \hat{w}_k)\}_{k=1}^N \quad \{(\hat{w}_k, y_k)\}_{k=1}^N$$

Parameter estimation of static nonlinear block

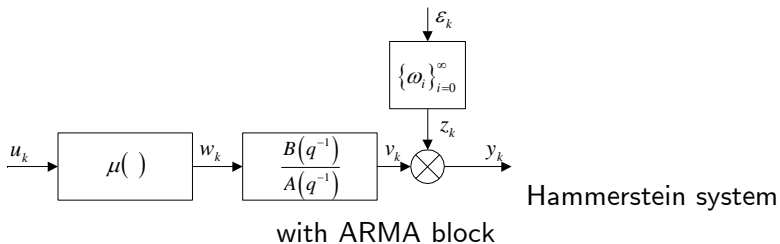
Stage 1 (non-parametric): Using observations $\{(u_k, y_k)\}_{k=1}^M$, for N_0 fixed points $\{\bar{u}_n; n = 1, 2, \dots, N_0\}$ estimate $\{w_n = \mu(\bar{u}_n, c^*); n = 1, 2, \dots, N_0\}$

$$\hat{w}_{k,M} = \frac{\sum_{k=1}^M y_k K\left(\frac{u-u_k}{h(M)}\right)}{\sum_{k=1}^M K\left(\frac{u-u_k}{h(M)}\right)}, \quad \text{or} \quad \hat{w}_{k,M} = \frac{\sum_{i=0}^{q(M)} \hat{\alpha}_{i,M} \varphi_i(u)}{\sum_{i=0}^{q(M)} \hat{\beta}_{i,M} \varphi_i(u)}$$

Stage 2 (parametric): Minimize the least squares criterion

$$\hat{Q}_{N_0,M}(c) = \sum_{n=1}^{N_0} [\hat{w}_{n,M} - \mu(\bar{u}_n, c)]^2 \rightarrow \min_c$$

Identification of ARMA block



$$v_k = b_0 w_k + \dots + b_s w_{k-s} + a_1 v_{k-1} + \dots + a_p v_{k-p}$$

$$\theta = (b_0, b_1, \dots, b_s, a_1, a_2, \dots, a_p)^T$$

$$\vartheta_k = (w_k, w_{k-1}, \dots, w_{k-s}, y_{k-1}, y_{k-2}, \dots, y_{k-p})^T$$

$$y_k = \vartheta_k^T \theta + \bar{z}_k, \quad \bar{z}_k = z_k - a_1 z_{k-1} - \dots - a_p z_{k-p}$$

$$Y_N = \Theta_N \theta + Z_N, \quad \Theta_N = (\vartheta_1, \dots, \vartheta_N)^T, \quad Z_N = (\bar{z}_1, \dots, \bar{z}_N)^T$$

Nonparametric instrumental variables

$$\hat{\theta}_{N,M}^{(IV)} = (\hat{\Psi}_{N,M}^T \hat{\Theta}_{N,M})^{-1} \hat{\Psi}_{N,M}^T Y_N$$

where

$$\hat{\Theta}_{N,M} = (\hat{\vartheta}_{1,M}, \dots, \hat{\vartheta}_{N,M})^T$$

$$\hat{\vartheta}_{k,M} = (\hat{w}_{k,M}, \dots, \hat{w}_{k-s,M}, y_{k-1}, \dots, y_{k-p})^T$$

$$\hat{\Psi}_{N,M} = (\hat{\psi}_{1,M}, \dots, \hat{\psi}_{N,M})^T$$

$$\hat{\psi}_{k,M} = (\hat{w}_{k,M}, \dots, \hat{w}_{k-s,M}, \hat{w}_{k-s-1,M}, \dots, \hat{w}_{k-s-p,M})^T$$

Limit properties

Static nonlinear block

$$\widehat{R}_M(\bar{u}_n) = R(\bar{u}_n) + O(M^{-\tau}) \implies \widehat{c}_{N_0, M} = c^* + O(M^{-\tau})$$

Linear dynamic block

$$\left| \widehat{R}_M(u) - R(u) \right| = O(M^{-\tau}) \implies \left\| \widehat{\theta}_{N, M}^{(IV)} - \theta \right\| = O(N^{-\min(\frac{1}{2}, \alpha)})$$

$NM^{-\tau} \rightarrow 0, \quad M \sim N^{(1+\alpha)/\tau}$

Identification under short measurement sequence

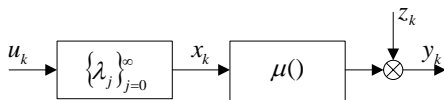
Semi-parametric approach

$$\hat{\mu}_1(u) = \hat{p}(u) + \frac{\sum_{k=1}^N (y_k - \hat{p}(u)) K\left(\frac{u - u_k}{h_N}\right)}{\sum_{k=1}^N K\left(\frac{u - u_k}{h_N}\right)}$$

$$\hat{\mu}_2(u) = \lambda_N \hat{p}(u) + (1 - \lambda_N) \hat{\mu}(u)$$

$$\lambda_N \rightarrow 0, \text{ as } N \rightarrow \infty$$

A censored sample mean approach



Wiener system

$$\delta_k(x) \triangleq \sum_{j=0}^{k-1} |u_{k-j} - x| \lambda^j$$

$$\hat{\mu}_M(x) = \frac{\sum_{k=1}^M y_k \cdot K\left(\frac{\delta_k(x)}{h(M)}\right)}{\sum_{k=1}^M K\left(\frac{\delta_k(x)}{h(M)}\right)}$$

Consistency conditions

Theorem

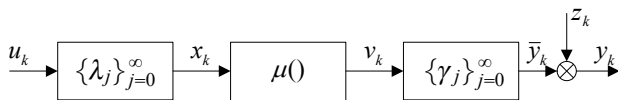
If $h(M) = d(M) \log_{\lambda} d(M)$, as $d(M) = M^{-\gamma(M)}$ and $\gamma(M) = (\log_{1/\lambda} M)^{-w}$, then for each $w \in (\frac{1}{2}, 1)$ it holds that

$$\lim_{M \rightarrow \infty} E (\hat{\mu}_M(x) - \mu(x))^2 = 0$$

Two-stage parameter estimation

$$Q_{N_0, M}(c) = \sum_{i=1}^{N_0} \left(\hat{\mu}_M(x^{(i)}) - \mu(x^{(i)}, c) \right)^2$$
$$\hat{c}_{N_0, M} = \arg \min_c Q_{N_0, M}(c)$$

Wiener-Hammerstein system



Wiener-Hammerstein (L-N-L sandwich) system

$$\hat{\mu}_N^{(1)}(x) = \frac{\sum_{k=1}^N y_k \cdot K\left(\frac{\sum_{j=0}^k |u_{k-j} - x| \lambda^j}{h(N)}\right)}{\sum_{k=1}^N K\left(\frac{\sum_{j=0}^k |u_{k-j} - x| \lambda^j}{h(N)}\right)}$$

$$\hat{\mu}_N^{(2)}(x) = \frac{\sum_{k=1}^N y_k \prod_{i=0}^p K\left(\frac{x - u_{k-i}}{h(N)}\right)}{\sum_{k=1}^N \prod_{i=0}^p K\left(\frac{x - u_{k-i}}{h(N)}\right)}$$

Identification of linear blocks

$$\hat{\mathcal{X}} = \left(\sum_{k=1}^N \phi_k \phi_k^T K \left(\frac{\Delta_k}{\eta} \right) \right)^{-1} \left(\sum_{k=1}^N \phi_k y_k K \left(\frac{\Delta_k}{\eta} \right) \right)$$

where

$$\{\mathcal{X}_i\} = \{\lambda_i\} * \{\gamma_i\}$$

$$\phi_k = \left(u_k, u_{k-1}, \dots, u_{k-(p+q)} \right)^T$$

$$\Delta_k = \max_{j=0,1,\dots,p+q} |u_{k-j}|$$

$$K \left(\frac{\Delta_k}{\eta} \right) = \begin{cases} 1, & \text{as } |\Delta_k| \leq \eta \\ 0, & \text{as } |\Delta_k| > \eta \end{cases}$$

Limit properties

Theorem

If $\eta \sim N^{-\alpha}$, where $\alpha \in \left(0, \frac{1}{p+q+3}\right)$ then

$$\widehat{\varkappa}_\tau \rightarrow \varkappa_\tau, \quad \tau = 0, 1, \dots, p+q$$

with probability 1 as $N \rightarrow \infty$, where $\varkappa_\tau = \lambda_\tau * \gamma_\tau$.

