Chtiba Reda

AutoRegressive-Moving-Average with Exogenous inputs (ARMAX)

Predictive Error Method

Implementation

PEM with Momentum

Prediction Error Method With Momentum

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2022.05.19

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PEM with Momentum The ARMAX Model , is used to describe certain dynamics that have a linear input-output mechanism. It can be given in this form:

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$$y(t) = rac{B(q^{-1})}{A(q^{-1})}u(t) + rac{C(q^{-1})}{A(q^{-1})}e(t)$$
 (1,1)

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Where y(t) is the output , e(t),u(t) is the input and A,B,C are

Lag-Polynomials

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Where y(t) is the output , e(t),u(t) is the input and A,B,C are

$$A(q^{-1}) = 1 + a_1q^{-1} + \ldots + a_{n_a}q^{-n_a}$$

Lag-Polynomials $B(q^{-1}) = 1 + b_1q^{-1} + \ldots + b_{n_b}q^{-n_b}$
 $C(q^{-1}) = 1 + c_1q^{-1} + \ldots + c_{n_c}q^{-n_c}$

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Components of the PEM

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PEM with Momentum

Components of the PEM

•Model choice: ARMAX, where the shocks e(t) are W.N with constant variance.

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•Predictor and Prediction Error:

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Components of the PEM

•Model choice: ARMAX, where the shocks e(t) are W.N with constant variance.

•Predictor and Prediction Error:

$$\hat{y}(t|t-1, heta)=\Big(1-rac{A(q^{-1}, heta)}{C(q^{-1}, heta)}\Big)y(t)+rac{B(q^{-1}, heta)}{C(q^{-1}, heta)}u(t)$$

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Components of the PEM

•Model choice: ARMAX, where the shocks e(t) are W.N with constant variance.

•Predictor and Prediction Error:

$$egin{aligned} \hat{y}(t|t-1, heta) &= \Big(1-rac{A(q^{-1}, heta)}{C(q^{-1}, heta)}\Big)y(t)+rac{B(q^{-1}, heta)}{C(q^{-1}, heta)}u(t)\ &\epsilon(t, heta) &= rac{A(q^{-1}, heta)}{C(q^{-1}, heta)}y(t)-rac{B(q^{-1}, heta)}{C(q^{-1}, heta)}u(t) \end{aligned}$$

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Components of the PEM

•Model choice: ARMAX, where the shocks e(t) are W.N with constant variance.

•Predictor and Prediction Error:

$$\hat{y}(t|t-1,\theta) = \left(1 - \frac{A(q^{-1},\theta)}{C(q^{-1},\theta)}\right)y(t) + \frac{B(q^{-1},\theta)}{C(q^{-1},\theta)}u(t)$$
$$\epsilon(t,\theta) = \frac{A(q^{-1},\theta)}{C(q^{-1},\theta)}y(t) - \frac{B(q^{-1},\theta)}{C(q^{-1},\theta)}u(t)$$

•Criterion:

$$V_N(heta) = rac{1}{N}\sum_{t=1}^N \epsilon(t, heta)^2$$

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$$A(q^{-1},\theta) = B(q^{-1},\theta)$$

$$\epsilon(t,\theta) = \frac{A(q^{-1},\theta)}{C(q^{-1},\theta)}y(t) - \frac{B(q^{-1},\theta)}{C(q^{-1},\theta)}u(t)$$

•Criterion:

$$V_N(\theta) = rac{1}{N} \sum_{t=1}^N \epsilon(t, \theta)^2$$

•Constraint set on θ :

$$\mathcal{D} = \{\theta | B(0) = 0, C(0) = 1, |c_i| < 1 \quad \forall i = 2, ..., n_c \}$$

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PEM with Momentum •Consistency :

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PEM with Momentum

•Consistency : If u(t) and y(t) are stationary, that is
$$|a_i| < 1 \quad \forall i = 2, ..., n_a$$
 and $|b_i| < 1 \quad \forall i = 2, ..., n_b$.

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PEM Estimate $\hat{ heta}$ is consistent.

•Asymptotic Distribution: If the Hessian of the Criterion is non-singular, Then:

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•Asymptotic Distribution: If the Hessian of the Criterion is non-singular, Then:

$$\sqrt{N}(\hat{\theta}_{N} - \theta_{0}) \xrightarrow{dist} \mathcal{N}(0, P)$$
Where $P = \Lambda \left[\mathsf{E}[\psi(t, \theta_{0})\psi(t, \theta_{0})^{T}] \right]$

Such that , Λ is the Covariance Matrix associated with e(t), θ_0 is the true parameter and ψ is the operator acting on $\epsilon(t,\theta)$ given by $\psi(t,\theta) = -\left[\frac{\partial\epsilon(t,\theta)}{\partial\theta}\right]^T$

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$\epsilon(t,\theta)$ does not depend on θ linearly. \Rightarrow

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PEM with Momentum $\epsilon(t,\theta)$ does not depend on θ linearly. $\Rightarrow \hat{\theta} = \underset{\theta \in \mathcal{D}}{\arg\min V_N(\theta)}$ does not have an analytical form. \Rightarrow

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However, if N is large \Rightarrow

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$$\hat{\theta}_{k+1} = \hat{\theta}_k + \alpha_k \Big[\frac{2}{N} \sum_{t=1}^N \psi(t, \theta_k) \psi(t, \theta_k)^T \Big]^{-1} \Big[\frac{2}{N} \sum_{t=1}^N \epsilon(t, \theta_k) \psi(t, \theta_k) \Big]$$

Where α_k is a gain coefficient.

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PEM with Momentum We simulate N=1000 output from true system:

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PEM with Momentum We simulate N=1000 output from true system:

$$(1-0.8q^{-1}) y(t) = (0.7q^{-1}) u(t) + (1+0.8q^{-1}) e(t)$$

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$$(1 - 0.8q^{-1}) y(t) = (0.7q^{-1}) u(t) + (1 + 0.8q^{-1}) e(t)$$

Where the input signal u(t) is W-N,taking value ± 1 with one delay, independent from the W-N e(t) with variance $\lambda^2 = 1$

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Where the input signal u(t) is W-N,taking value ± 1 with one delay, independent from the W-N e(t) with variance $\lambda^2=1$ After Simulation, we store the data.Then we would like to apply the PEM on the data to see whether the estimated $\hat{\theta}$ is close to the true one or not .

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Below, is a figure that shows the evolution of the estimated parameters in 70 iterations.

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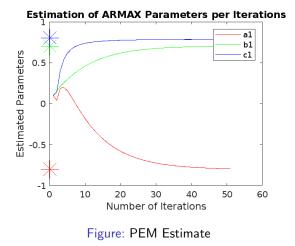
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PEM with Momentum We would like to think of a way to improve this algorithm,

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PEM with Momentum We would like to think of a way to improve this algorithm, a natural way to do so is to add the Momentum part to the Gauss-Newton Algorithm.

PEMM

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Where β_k is a gain coefficient.

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PEMM

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Where β_k is a gain coefficient. The table below, shows some numerical experiments using the PEMM, for various values of β_k and similar conditions to what we had for the PEM experiment.

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Table: Comparing PEM with Momentum for different β_k

β_k	$\hat{ heta}_{70}$
$\ge 10^{-3}$	NAN
$\leq 10^{-3}$	$\approx \left[-0.8, 0.7, 0.8\right]$

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