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Analyzing Iterations in Identification with Application to Nonparametric $H_\infty$-norm Estimation

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Abstract: In the last decades, many iterative approaches in the field of system identification for control have been proposed. Many successful implementations have been reported, despite the lack of a solid analysis with respect to the convergence and value of these iterations. The aim of this paper is to present a thorough analysis of a specific iterative algorithm that involves nonparametric $H_\infty$-norm estimation. The pursued approach involves a novel frequency domain approach that appropriately deals with additive stochastic disturbances and input normalization. The results of the novel convergence analysis are twofold: i) the presence of additive disturbances introduces a bias in the estimation procedure, and ii) the iterative procedure can be interpreted as experiment design for $H_\infty$-norm estimation, revealing the value of iterations and limits of accuracy in terms of the Fisher information matrix. The results are confirmed by means of a simulation example.

1. INTRODUCTION

In the last decades, many iterative approaches have been proposed in the fields of system identification and control design. Examples of such iterative approaches include iterative learning control (ILC) [Bristow et al., 2006], iterative feedback tuning [Hjalmarsson, 2002], and iterative identification and control [Albertos and Sala, 2002]. Although many successful implementations of these approaches have been reported in the literature, the application of these techniques has met mixed outcomes. Indeed, analyses of specific approaches have pointed out several shortcomings. For instance, in the case of iterative identification and control design, the stationary point of the iterative algorithm may not be a local minimum of the objective function as is pointed out in Hjalmarsson et al. [1995]. Furthermore, the iterations in these approaches may be divergent, see, e.g., Albertos and Sala [2002, Sec. 9.3]. Finally, the value of iterations in these approaches has been questioned in, e.g., Bölting and Mäkiä [1998].

Recently, an iterative approach for nonparametric $H_\infty$-norm estimation has been proposed in Hjalmarsson [2005, Sec. 12.2] and further extended in Wahlberg et al. [2010a]. A relevant application of $H_\infty$-norm estimation includes model error modeling, since reliable robust control design methodologies are available that consider model errors as $H_\infty$-norm bounded operators. In contrast to most model error modeling techniques, including Hakvoort and Van den Hof [1997], Ljung [1999a], the approach presented in [Hjalmarsson, 2005, Sec. 12.2] does not require the estimation of an intermediate parametric model. However, in Hjalmarsson [2005, Sec. 12.2], the input to the system is iteratively determined, followed by a nonparametric estimation of the $H_\infty$-norm from the measured data of two experiments. An essential property of the iterative procedure is that it is known to converge to the global optimum with an exponential rate of convergence in the noise-free case, since in this case it coincides with a power iteration [Golub and Van Loan, 1996, Section 8.2].

Although several successful applications of iterative nonparametric $H_\infty$-norm estimation have already been reported, including Barenthin et al. [2005], Barenthin et al. [2006], convergence of the considered algorithm has not been analyzed in a stochastic framework. Indeed, when performing experiments on any realistic system, measurement errors and unmeasured disturbances inevitably contaminate the observation. A suitable approach to model these measurement errors and unmeasured disturbances is to consider these in a stochastic framework. The aim of the present paper is to thoroughly analyze convergence, bias, accuracy, and the value of iterations of a certain iterative nonparametric norm estimation algorithm that is subject to additive stochastic disturbances.

Related analyses of power iterations that are implemented in an imperfect environment are reported in Krasulina [1970] and Oja and Karhunen [1985], where the involved matrices are considered random. However, the results for the case of random matrices cannot be directly extended to the case of additive stochastic disturbances that is relevant for the considered system identification problem. Similarly, in, e.g., Golub and Van Loan [1996], the effect of round-off errors in power iterations has been discussed. However, such round-off errors do not provide a suitable description for additive disturbances.

The main contribution of the present paper is a thorough stochastic analysis of a certain iterative nonparametric norm estimation procedure. As specific contributions of the paper: i) a novel algorithm is proposed for $H_\infty$-norm estimation; ii) a novel algorithm is proposed for $H_\infty$-norm estimation.
estimation based on a single experiment. In contrast, two experiments are required in Wahlberg et al. [2010a]. ii) the value of iterations is established through the Fisher information matrix, revealing that the iterative algorithm can be interpreted as an optimal experiment design approach for $H_{\infty}$-norm estimation for both parametric and nonparametric identification methodologies.

The outline of the paper is as follows. In Sec. 2, a nonparametric $H_{\infty}$-norm estimation algorithm is presented, where the estimation of the norm is based on a single experiment. In Sec. 3, the limit spectra are derived and their convergence is analyzed. Then, in Sec. 4, the derived spectra are employed for a bias analysis of the resulting estimator and for a derivation of the information matrix. The derived results are illustrated by means of an example in Sec. 5. In Sec. 6, concluding remarks are presented. Several proofs are omitted due to space limitations. These proofs are available in Oomen et al. [2011].

2. ITERATIVE NONPARAMETRIC $H_{\infty}$-NORM ESTIMATION

Throughout, the asymptotically stable SISO LTI system

$$y_t = G(z)u_t + e_t = \sum_{k=0}^{\infty} g_k u_{t-k} + e_t, \quad t = 1, 2, \ldots, (1)$$

is considered, see also Fig. 1, where $u_t$ denotes the quasi stationary input to the system [Ljung, 1999b], $y_t$ is the output, and $e_t$ is white noise of variance $\lambda_e > 0$, representing measurement noise or a disturbance term, with $e_t$ and $u_t$ independent.

One of the key properties of the $H_{\infty}$-norm, i.e., $\|G\|_{\infty} = \sup_{e \in (-\pi, \pi)} |G(e^{j\omega})|$, is that it equals the $\ell_2$-induced norm, since

$$\|G(z)\|_{\infty} = \sup_{u \in \mathcal{U}} \|y\|_2 / \|u\|_2$$

where $\|x\|_2 := (\sum_{i=1}^{\infty} x_i^2)^{1/2}$. The characterization of the $H_{\infty}$-norm in (2) is useful for several reasons. Firstly, it is an induced norm and thus enables the representation of model uncertainty by $H_{\infty}$-norm bounded operators. Secondly, (2) is at the basis of the nonparametric $H_{\infty}$-norm estimation algorithms that are presented in this paper.

The following algorithm is the main result of this section and enables nonparametric $H_{\infty}$-norm estimation.

Algorithm 1. Apply the following sequence of steps:

1. Let $n = 1$ and generate an input sequence $u^{(1)} := [u_1^{(1)} \cdots u_N^{(1)}]^T$ such that $\|u^{(1)}\|_2 / \sqrt{N} = 1$.
2. Apply $u^{(n)}$ to the system, yielding $y^{(n)} := [y_1^{(n)} \cdots y_N^{(n)}]^T$.
3. Time reverse the sequence $y^{(n)}$, i.e., determine $\tilde{g}^{(n)} := [\tilde{y}_N^{(n)} \cdots \tilde{y}_1^{(n)}]^T$, and generate $u^{(n+1)} = \tilde{g}^{(n)} / \mu^{(n)}$, where the normalization $\mu^{(n)}$ is defined below.
4. Let $n \to n + 1$ and go to step (2).
This phenomenon is introduced solely by the finite sample effect. Indeed, for infinite \(N\), \(G\) is an infinite matrix representing a Toeplitz operator on \(\ell_2\), whose spectral radius is \(\| G \|_{\infty} \), see, e.g., [Böttcher and Grudsky, 2005, Corollary 1.12]. Note that the analysis in Section 3 is performed in the frequency domain in terms of power spectra, and leads to the same conclusions regardless of whether the power iterations are applied to \(G^T G\) or \(G\).

**Remark 4.** To point out the relation between the presented approach, i.e., Algorithm 1 in conjunction with the estimator (4), and the \(\ell_2\)-induced norm characterization of the \(\mathcal{H}_\infty\)-norm, i.e., (2), as well as to clarify the relation with the algorithm in Wahlberg et al. [2010a] that requires two experiments for nonparametric \(\mathcal{H}_\infty\)-norm estimation, observe that

\[
\sup_{u(n) \in \ell_2} \frac{\|y(n)\|_2}{\|u(n)\|_2} = \sup_{u(n) \in \ell_2} \frac{y(n)^T y(n)}{u(n)^T u(n)} = \sup_{u(n) \in \ell_2} \frac{u(n)^T G^T G u(n)}{u(n)^T u(n)} \quad (7)
\]

which is clearly maximal if \(u(n)\) is in the eigenvector direction corresponding to \(\lambda_{\max}(G^T G)\). In Wahlberg et al. [2010a], a power iteration is applied to \(G^T G\) to estimate the maximum gain, which requires two experiments and two time reversal operations. Specifically, due to the Toeplitz structure of \(G\), \(G^T = TG^T\), hence \(G^T G = T G^2 T\). To show that the estimator gain for \(n \to \infty\) is equivalent in the noise-free case, observe that since \(G_H\) is symmetric, it can be factorized as \(G_H = QAQ^T\), where \(Q\) is orthonormal and \(A\) is a diagonal matrix containing the eigenvalues of \(G_H\). As a result, \(G^T G = Q A Q^T\), hence \(G^T G\) has eigenvalues \(A^2\).

**Remark 5.** The eigenvalues of \(G_H\), unlike those of \(G^T G\), see Remark 4, are not guaranteed to be positive. As a result, \(\beta_{2n}^2 = \frac{|u(n)^T G y(n)|^2}{\|u(n)\|^2}\) may have a slow transient. Specifically, an oscillatory transient may arise if the first and second largest eigenvalues of \(G_H\) have different sign. For this reason, the estimator in Wahlberg et al. [2010a] can be adapted to deal with the considered normalization in the present paper that is applied after each experiment, see Algorithm 1, in which case

\[
\beta_{2n}^2 = \sqrt{\mu (n-1)} |u(n-1)^T G y(n)|. \quad (7)
\]

Estimator (7) may thus be preferable in the case where it is desired to determine the absolute value of the maximum eigenvalue. Specifically, the estimator \(\beta_{2n}^2\) corresponds to the square root of \(\lambda_{\max}(G_H^2) = \lambda_{\max}(G^T G)\) and thus to \(\lambda_{\max}(G_H^2)\). Since \(G_H^2 = G^2\) is positive semidefinite, \(\beta_{2n}^2\) does not suffer from a possible slow oscillatory transient. Note that the analysis in this paper also applies to \(\beta_{2n}^2\).

In the preceding analysis of Algorithm 1, it is assumed that \(\lambda_e = 0\), i.e., the noise-free situation. In the next section, a stochastic analysis is performed for \(\lambda_e > 0\). Then, in Sec. 4, the estimators (4) and (7) are analyzed in detail.

### 3. CONVERGENCE ANALYSIS

In this section, a convergence analysis of Algorithm 1 is presented in the case where additive stochastic disturbances are present, i.e., \(\lambda_e > 0\) in (1). First, expressions for the limit spectra are derived in Section 3.1, followed by a convergence analysis in Section 3.2.

#### 3.1 Limit Spectrum

In this section, Algorithm 1 is analyzed in the presence of noise, i.e., in the case where \(\lambda_e > 0\). The first step in the analysis is to assume that \(N \to \infty\), i.e., the number of data samples at each iteration tends to infinity. This enables an analysis in the frequency domain in terms of \(\Phi_u(e^{j\omega}) \in L_1([-\pi, \pi], R_+^\omega)\), i.e., the spectrum of \(u_t\) at iteration \(n\), see [Jüng, 1999b, Chapter 2] for an appropriate definition.

It is important to notice that, for a finite \(N\), the effect of the time reversal operation \(T\), which can be described as a combination of a time shift (by \(N\) samples) plus a time inversion, \(t \mapsto -t\), has no effect on the spectrum of a quasi-stationary signal. This means that the time reversal operation can be omitted in a frequency domain analysis of the power iterations method, see also Remark 3.

**Lemma 6.** Consider Algorithm 1 applied to the system \(G\) in (1), where \(\lambda_e > 0\). Then, for \(N \to \infty\),

\[
\Phi_u^{(n+1)}(\omega) = \frac{1}{\pi} \int_{-\pi}^{\pi} |G(e^{j\omega})|^2 \Phi_u^{(n)}(\omega) d\omega + \lambda_e \quad (8)
\]

**Proof.** Combining (1) and Algorithm 1 yields

\[
u^{(n+1)} = \frac{1}{\mu(k)} \left( G_H u + e^{(n)} \right),\quad (9)
\]

where \(\mu(k)\) is defined in (3). Independence of \(u(n)\) and \(e(n)\) implies that

\[
\Phi_u^{(n+1)}(\omega) = \frac{1}{\mu^2} \left( G(e^{j\omega})^2 \Phi_u^{(n)}(\omega) + \lambda_e \right). \quad (8)
\]

Finally, applying Parseval’s relation to \(\mu(k)\) yields (8). □

Next, fixed points of the function (8) are analyzed.

**Theorem 7.** The function (8) has a unique fixed point \(\Phi_u^{(\infty)}\), which is given by

\[
\Phi_u^{(\infty)}(\omega) = \frac{\lambda_e}{\mu^2 - |G(e^{j\omega})|^2}, \quad (9)
\]

where \(\mu > 0\) satisfies

\[
\frac{1}{\lambda_e} = \frac{1}{2\pi} \int_{-\pi}^{\pi} \frac{1}{\mu^2 - |G(e^{j\omega})|^2} d\omega. \quad (10)
\]

**Proof.** Every such fixed point \(\Phi_u^{(\infty)} \in L_1([-\pi, \pi], R_+^\omega)\) satisfies the equation

\[
\Phi_u^{(\infty)}(\omega) = \frac{1}{\mu^2} |G(e^{j\omega})|^2 \Phi_u^{(\infty)}(\omega) + \lambda_e \quad (11)
\]

Denoting

\[
\mu^2 = \frac{1}{2\pi} \int_{-\pi}^{\pi} |G(e^{j\omega})|^2 \Phi_u^{(\infty)}(\omega) d\omega + \lambda_e \quad (12)
\]

and solving (11) for \(\Phi_u^{(\infty)}\) yields (9). In addition, the resulting \(\Phi_u^{(\infty)}\) is unique. Next, to show (10), note that substitution of (9) into (12) yields

\[
\mu^2 = \frac{1}{2\pi} \int_{-\pi}^{\pi} \lambda_e |G(e^{j\omega})|^2 + \lambda_e (\mu^2 - |G(e^{j\omega})|^2) d\omega
\]

\[
= \mu_e^2 \lambda_e \quad (13)
\]

Next, by nonnegativity of \(\Phi_u^{(\infty)}(\omega)\), the latter equation directly implies the desired result (10). □
The result of Theorem 7 enables the derivation of the following properties of \( \Phi(\infty) \) and \( \mu \) as a function of \( \lambda_e \).

**Theorem 8.** Consider the iteration (8), where the fixed points satisfy the results in Theorem 7. Then,

1. \( \mu \geq \|G\|_\infty \).
2. \( \Phi^{(\infty)}(\omega) \) attains its (finite) maximum at the frequencies where \( |G(e^{j\omega})|^2 \) is maximum.
3. \( \Phi^{(\infty)}(\omega) \) attains its (non-zero) minimum at the frequencies where \( |G(e^{j\omega})|^2 \) is minimum. Furthermore, if \( |G(e^{j\omega})|^2 \to 0 \) at some \( \omega \), then \( \Phi^{(\infty)}(\omega) \to \lambda_e/\mu^2 \).
4. \( \mu \) is a continuous and strictly increasing function of \( \lambda_e \), such that \( \mu \to \|G\|_\infty \) as \( \lambda_e \to 0 \), and \( \mu \to \infty \) as \( \lambda_e \to \infty \).

The behavior of \( \mu \) for \( \lambda_e \ll 1 \) is analyzed next.

**Theorem 9.** Let \( G \in \mathcal{H}_\infty(\mathbb{E}) \), where \( \mathbb{E} := \{ z \in \mathcal{C} : |z| \geq 1 \} \), be such that \( |G(e^{j\omega})|^2 \) has a single global maximum in \([0, \pi]\) at, say, \( \omega \).

\[
\frac{1}{\lambda_e} = \frac{1}{2\pi} \int_{-\pi}^{\pi} \mu^2(\lambda_e) \left| |G(e^{j\omega})|^2 \right| d\omega,
\]

where \( \lambda_e > 0 \) and \( \mu : \mathbb{R}_+^n \to \|G\|_\infty, \infty \). Then,

\[
\mu^2(\lambda_e) = \|G\|_\infty^2 + \frac{2}{\pi} \lambda_e^2 + o(\lambda_e^2),
\]

where \( H_\mu := -\partial^2|G(e^{j\omega})|^2/\partial \omega^2|_{\omega=\omega} \).

**Theorem 10.** Let \( \Phi^{(1)}(\omega) \in \mathcal{L}_\infty([-\pi, \pi], \mathbb{R}_+^n) \) be such that \( \text{inf}_\omega \Phi^{(1)}(\omega) > 0 \). Then, the sequence \( \{\Phi^{(n)}(\omega)\}_{n \in \mathbb{N}} \) generated by (8) converges in the \( \mathcal{L}_\infty \) norm to \( \Phi^{(\infty)}(\omega) \) in (9).

### 4. PROPERTIES OF THE ESTIMATOR

In this section, the results of Section 3 are employed to analyze Algorithm 1 in Section 2, specifically in Section 4.1, the bias of estimators 4 and (7) is analyzed, followed by an analysis of the value of iterations in terms of the Fisher information matrix in Section 4.2.

#### 4.1 Bias Analysis

In this section, the bias of the nonparametric gain estimate is analyzed. Throughout this section, the emphasis is on the estimator in (7), since this enables a comparison with the results in Wahlberg et al. [2010a], where a similar estimator modulates the normalization is considered. In Wahlberg et al. [2010a], it is shown that this estimator is unbiased, provided that \( u(n-1) \) is in the eigenvector direction corresponding to the largest eigenvalue of \( G^T G \), which in the case \( N \to \infty \) corresponds to a sinusoidal signal. These results are thus in line with the result of Theorem 2 and the discussion in Remark 4.

However, the results in Theorem 8 reveal that the input does not converge to the eigenvector direction corresponding to the largest eigenvalue of \( G^T G \) if \( \lambda_e > 0 \), since even for \( N \to \infty \) the input \( u(n) \) does not converge to a sinusoid. Hence the bias analysis in Wahlberg et al. [2010a] of the power iteration procedure in a stochastic framework is incomplete. The following result enables a more detailed analysis of the estimator \( \beta^{(\infty)}(\omega) \).

**Lemma 11.** Consider the estimator (7). Then, for \( N \to \infty, \)

\[
E \left\{ \beta^{(\infty)}(\omega) \right\} = \frac{1}{2\pi} \int_{-\pi}^{\pi} |G(e^{j\omega})|^2 \Phi_u^{(\infty)}(\omega) d\omega. \tag{13}
\]

**Proof.** Observe that for \( N \to \infty \), the numerator and denominator in (7) can be recast as a sample cross-spectrum and a sample spectrum, respectively. Hence, taking expectations,

\[
E \left\{ \beta^{(n)}(\omega) \right\} = \frac{1}{2\pi} \int_{-\pi}^{\pi} \Phi_u^{(n)}(\omega) d\omega = \frac{1}{2\pi} \int_{-\pi}^{\pi} \frac{1}{\mu(n-1)}|G(e^{j\omega})|^2 \Phi_u^{(n-1)}(\omega) d\omega,
\]

which equals (13). \( \square \)

Lemma 11 in conjunction with Theorem 8 reveals several qualitative results with respect to the bias of the limit estimator \( \beta^{(\infty)}(\omega) \). Indeed, note that for \( \lambda_e > 0 \), \( \Phi^{(\infty)}(\omega) \) is a smoothed Dirac delta function. Clearly, this implies that

\[
E \left\{ \beta^{(\infty)}(\omega) \right\} < \|G\|_\infty^2 \text{ for } \lambda_e > 0, \tag{14}
\]

hence the power iterations result in a biased estimate of the \( \mathcal{H}_\infty \) norm if \( \lambda_e > 0 \). Similarly, observe that if \( \lambda_e \to 0 \), then \( \Phi_u^{(\infty)}(\omega) \) tends to a Dirac delta function. Exploiting the sifting property of the Dirac delta function, and the fact that the variance of \( \beta^{(n)}(\omega) \) goes to zero as \( \lambda_e \to 0 \), reveals that

\[
\beta^{(\infty)}(\omega) \to \|G\|_\infty^2 \text{ in mean, as } \lambda_e \to 0,
\]

hence the estimator is unbiased if \( \lambda_e \to 0 \).

A quantitative expression of the asymptotic bias of the power method is given in the following theorem.

**Theorem 12.** Consider the estimator (7). Then, for \( N \to \infty, \)

\[
E \left\{ \beta^{(\infty)}(\omega) \right\} = \|G\|_\infty^2 - \lambda_e + \frac{2}{\pi} \lambda_e^2 + o(\lambda_e^2). \tag{15}
\]

**Proof.** Lemma 11 reveals that for \( n \to \infty, \)

\[
E \left\{ \beta^{(\infty)}(\omega) \right\} = \frac{1}{2\pi} \int_{-\pi}^{\pi} |G(e^{j\omega})|^2 \Phi_u^{(\infty)}(\omega) d\omega. \tag{15}
\]

Combining (15) and (12) yields

\[
\mu^2 = E \left\{ \beta^{(\infty)}(\omega) \right\} + \lambda_e.
\]

Next, rearranging and applying the result of Theorem 9 gives the following asymptotic expression for the bias:

\[
E \left\{ \beta^{(\infty)}(\omega) \right\} = \mu^2 - \lambda_e = \|G\|_\infty^2 - \lambda_e + \frac{2}{\pi} \lambda_e^2 + o(\lambda_e^2),
\]

which concludes the proof. \( \square \)

Theorem 12 shows that the asymptotic bias, \( E \left\{ \beta^{(\infty)}(\omega) \right\} - \|G\|_\infty^2 \), is dominated by \( -\lambda_e \) in the small noise regime.
Equivalently, $E \{ [\beta(\infty)] \} - \| G \|_{\infty} = -(1/2) \lambda_e \| G \|_{-1}^{\infty} + o(\lambda_e)$, which corroborates the previous analysis.

Furthermore, Theorem 12 shows that the normalization factor, $\mu^{(n)}$, which as $n, N \to \infty$ is equal to $\mu$, might be a better estimator of $\| G \|_{\infty}$ for small $\lambda_e$ in terms of bias. Indeed, observe that $\mu^{(n)}$ can be interpreted as a direct estimator for (2) by forming the product $[y^{(n)}]^T y^{(n)}$.

4.2 Fisher Information Matrix per Iteration

The value of iterations is immediate if the nonparametric estimator (7) is used, since Theorem 2 reveals that the estimate converges to the $H_\infty$-norm for $\lambda_e = 0$ and an increasing number of iterations. However, the value of power iterations has not yet been investigated in the general case where possibly another estimator is used. Independent of the specific estimator, the limit of accuracy of the power iterations method can be analyzed through the asymptotic information matrix. Here, an analysis is performed where an underlying parametric model is considered.

Specializing to the prediction error framework, let $G(z, \theta)$ be a parametric model structure. Assuming that there exists a $\theta_o$, called the true parameter, such that $G(z, \theta_o) = G$, where $G$ denotes the true system, then under mild conditions

$$\sqrt{N}(\hat{\theta}_N - \theta_o) \xrightarrow{d} N(0, P_0),$$

see, e.g., [Jung, 1999b, Chapter 9]. The prediction error estimator turns out to be asymptotically efficient, i.e., the asymptotic covariance matrix $P_0$ equals the inverse of the (Fisher) information matrix, which is given by

$$I_\theta = E \left\{ \psi_1 \Lambda^{-1} \psi_1^T \right\}.$$

In addition,

$$\psi_t = -\frac{\partial \psi_t^T}{\partial \theta^{\dagger}} |_{\theta = \theta_o},$$

where $\varepsilon_t$ is the prediction error

$$\varepsilon_t = y_t - \hat{y}_{t|t-1}.$$

Evaluating the Fisher information matrix for the system (1) and Algorithm (1) yields the following result.

**Lemma 13.** Consider system (1) and the power iterations algorithm 1. Then,

$$I_\theta = \sum_{k=1}^{n} f^{(k)}_u,$$

where $f^{(k)}_u = \frac{1}{\pi \lambda_e} \int_{-\pi}^{\pi} G'(e^{j\omega}) \Phi^{(k)}_u(\omega) \left( G'(e^{-j\omega}) \right)^T d\omega$ and $G'(z) := \partial G(z, \theta)/\partial \theta |_{\theta = \theta_o}$.

**Proof.** Using (1) and (18), $\varepsilon_t = y_t - \hat{y}_{t|t-1}$. Clearly,

$$\frac{\partial \varepsilon_t}{\partial \theta^{\dagger}} = -G'(q)u^{(k)}_t.$$

Next, using (17),

$$\psi_t = \left[ \frac{\partial \psi_1^{(1)}}{\partial \theta^{\dagger}} \quad \frac{\partial \psi_1^{(2)}}{\partial \theta^{\dagger}} \quad \vdots \quad \frac{\partial \psi_1^{(k)}}{\partial \theta^{\dagger}} \right] = G'(q)U_t,$$

where $U_t := \left[ u_1^{(1)} \quad u_1^{(2)} \quad \vdots \quad u_1^{(k)} \right]$. Next, using (16) and Parseval's relation,

$$I_\theta = E \left\{ \psi_1 \Lambda^{-1} \psi_1^T \right\} = \frac{1}{\lambda_e} E \left\{ \psi_1^2 \right\} = \frac{1}{2\pi \lambda_e} \int_{-\pi}^{\pi} G'(e^{j\omega}) \Phi_U(\omega) \left( G'(e^{-j\omega}) \right)^T d\omega.$$

Note that here

$$\Phi_U(\omega) = \sum_{r=-\infty}^{\infty} R_U(\omega) e^{-jr\omega},$$

and

$$R_U(\tau) = \lim_{N \to \infty} \frac{1}{N} \sum_{r=1}^{N} \sum_{k=1}^{n} u_{r+k}^{(k)} u_{r+k}^{(k)} = \sum_{k=1}^{n} R^{(k)}(\tau).$$

Next, combining (20) and (21) yields (19).

Several interesting observations can be made with respect to Lemma 13. Firstly, it is observed that the Fisher information matrix for iterative schemes satisfies an additivity property, see (19), i.e., additional experiments can only increase information about the system. This is consistent with Fisher's original requirements for the definition of information [Porat, 1994, page 50]. Secondly, due to the uniform convergence of $\Phi^{(n)}_u$, (19) divided by $n$ corresponds to a Cesáro sum, it holds in the asymptotic case where the number of experiments $n \to \infty$,

$$\lim_{n \to \infty} \frac{1}{n} \int_{-\pi}^{\pi} G'(e^{j\omega}) \Phi^{(n)}_u(\omega) \left( G'(e^{-j\omega}) \right)^T d\omega.$$
Finally, 1000 realizations of the iterative procedure are averaged, see Fig. 3 (right). It is observed that the bias increases for increasing $\lambda_c$. From Lemma 11, this can be understood when considering the smoothness of $G$ and the spectra in Fig. 2.

6. CONCLUSION

The results presented in this paper contribute to the analysis of the role of iterations in system identification for control. An approach for nonparametric $H_{\infty}$-norm estimation is presented that requires only one experiment for the estimation procedure. In addition, it is shown that for a nonparametric $H_{\infty}$-norm estimation through iterative experiments, (1) additive disturbances can introduce bias errors, and (2) iterative procedures can be interpreted as experiment design for $H_{\infty}$-norm estimation, and the value of iterations has been investigated by means of the Fisher information matrix. The analysis is based on a frequency domain approach, the novelty of the presented approach is that it addresses both (1) additive stochastic disturbances that represent measurement errors, and (2) the normalization of the input signal to account for input power constraints, which involves a nonlinear operation.

Future research includes the extension of the presented results in several directions. Firstly, it is shown in the present paper that the implementation of power iterations in the presence of stochastic disturbances results in bias errors. Presently, modifications of the input signal update, i.e., Step 3 in Algorithm 1, as well as the estimators (4) and (7) are being investigated to avoid these bias errors, e.g., by using data from old experiments through stochastic approximation. Secondly, extensions of the power iteration algorithm are being investigated that enable the nonparametric estimation of other system properties.

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