

DETECTION AND DIAGNOSIS OF CHANGES IN THE A.R. PART OF AN A.R.M.A.
 MODEL WITH NONSTATIONARY UNKNOWN M.A. COEFFICIENTS

M. Basseville, A. Benveniste, G. Moustakides, A. Rougée
 I.R.I.S.A. (CNRS & INRIA)
 Campus de Beaulieu
 35042 RENNES Cedex - France

Problem statement :

$$\text{Let } y_t = \sum_{i=1}^p a_i y_{t-i} + \sum_{j=0}^q b_j(t) e_{t-j} \quad (1)$$

be a scalar ARMA(p,q) model, where (e_t) is a gaussian white noise with constant variance σ_e^2 , and where the MA coefficients $(b_j(t))_j$ are time-varying, possibly subject to jumps. The problems to be solved are :

- i) given a single (long) record of observations $(y_t^0)_{0 \leq t \leq s}$, estimate the AR parameters, without using the unknown time-varying MA parameters ; then, calling "reference model" the AR part characterized by these estimated parameters,
- ii) given another record of $(y_t^1)_{0 \leq t \leq s}$, test whether the reference AR model still fit these new observations or has changed, again without knowing the (highly) time-varying MA coefficients ("global test") ;
- iii) decide which poles have changed, i.e. solve the diagnosis problem.

Notations :

For $i = 0,1$, let $R_k^i(s)$ be the empirical covariances :

$$R_k^i(s) = \sum_{t=0}^{s-k} y_{t+k}^i y_t^i \quad (k \geq 0) \text{ and } \mathcal{H}_{p+1,N}^i(s) \text{ the } (p+1) \times N \text{ empirical Hankel matrices :}$$

$$\mathcal{H}_{p+1,N}^i = \begin{pmatrix} R_{q-p+1}^i(s) & R_{q-p+2}^i(s) & \dots & R_{q-p+N}^i(s) \\ R_{q-p+2}^i(s) & \dots & \dots & \vdots \\ \vdots & \dots & \dots & R_{q+N}^i(s) \\ R_{q+1}^i(s) & \dots & \dots & \dots \end{pmatrix}$$

where $N \geq p$.

Theorem 1 [3] :

The least squares solution $\hat{\theta} \triangleq (a_i^0(s))_{1 \leq i \leq p}$ of the equation :

$$(-a_p - a_{p-1} \dots -a_1 \ 1) \mathcal{H}_{p+1,N}^0(s) = 0$$

is a consistent estimate of the true AR parameters, $\hat{\theta}_i$ the nonstationary case.

Precise conditions and proof (using the law of large numbers for martingales) can be found in [3]. In other words, the so-called instrumental variables method for identification is consistent even if the MA part is nonstationary, and thus solves problem i).

$$\text{Let be : } U_N^1(s) \triangleq (-a_p^0 \dots -a_1^0 \ 1) \mathcal{H}_{p+1,N}^1(s) \\ = \sum_{t=q+N}^s w_t Z_t$$

where : $w_t = y_t^1 - a_1^0 y_{t-1}^1 - \dots - a_p^0 y_{t-p}^1$ is the "moving average" part of the record (y_t^1) and $Z_t = (y_{t-q-1}^1 \dots y_{t-q-N}^1)'$. Let also be :

$$\hat{\Sigma}_N(s) = \sum_{t=q+N}^{s-q} \sum_{i=-q}^q w_t w_{t-i} Z_t Z_{t-i}'$$

Theorem 2 [5] :

. *Nonstationary law of large numbers* : $\hat{\Sigma}_N$ is a consistent estimate of the true covariance matrix Σ_N of U_N , namely : $\hat{\Sigma}_N^{-1}(s) \hat{\Sigma}_N(s) \xrightarrow{s \rightarrow \infty} I_N$, under both null hypothesis, i.e. the AR parameters are θ_0 , and local alternative hypothesis, i.e. the parameters are $\theta_0 + \frac{\delta\theta}{\sqrt{s}}$, where $\delta\theta$ is fixed.

. *Central limit theorem* : $\hat{\Sigma}_N(s)^{-1/2} \cdot U_N(s) \xrightarrow{s \rightarrow \infty} \mathcal{N}(0, I_N)$ under \mathbf{P}_{θ_0}

$$\Sigma_N(s)^{-1/2} \cdot (U_N(s) - \mathcal{H}_{p,N}^{-1}(s) \cdot \frac{\delta\theta}{\sqrt{s}}) \xrightarrow{s \rightarrow \infty} \mathcal{N}(0, I_N) \text{ under } \mathbb{P}_{\theta_0 + \frac{\delta\theta}{\sqrt{s}}}.$$

Precise conditions and proof (limit theorems for martingales) can be found in [5]. In other words, the use of the *local* approach for detecting changes ([4], [6], [2]) reduces problem ii) to the problem of detecting a change in the mean of a Gaussian process. A possible χ^2 test for solving ii) is thus :

$$t_0 = U_N' \Sigma_N^{-1} \mathcal{H}_{p,N}' (\mathcal{H}_{p,N} \Sigma_N^{-1} \mathcal{H}_{p,N}')^{-1} \mathcal{H}_{p,N} \Sigma_N^{-1} U_N \quad (2).$$

Let ψ be the set of the m ($\leq p$) poles to be monitored, and J be the $p \times m$ Jacobian matrix $J_{p,m} = \left(\frac{\partial a_i}{\partial \psi_j} \right)_{\{\psi_j\} = \psi_0}$.

diagnosis test (solving problem iii) is of the form (2) where $\mathcal{H}_{p,N}'$ is replaced by $\mathcal{H}_{p,N}' J_{p,m} (|1|)$. This approach allows, for example, separate monitoring of poles or subsets of poles, without knowing in advance which poles will actually change.

Extension to the vector case-applications to offshore platforms :

All these results are also valid in the *vector case*. See [3] and [8] for theoretical results. In [7] can be found numerical results (on real data) concerning the identification problem i) for vibrating characteristics of offshore platforms ; the main conclusion is that high order poles and modes are correctly identified. Results of simulations concerning the test ii) and diagnosis iii) problems in the scalar case can be found in [1] ; the main conclusion is that it is possible to detect and diagnose *small changes* (1 %) in eigenfrequencies, provided the sample size is large enough. Experimentations for the vector case are described in [9] and lead to discrimination between physically different changes.

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