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Closed-loop system identification via a tailor-made IV method

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Abstract

A bias-correction method for closed-loop identification, introduced in the literature as the bias-eliminated least squares (BELS) method [1], is shown to be equivalent to a basic instrumental variable estimator applied to a predictor for the closed-loop system. This predictor is a function of the plant parameters and the known controller. Corresponding to the related method using a least squares criterion, the method is referred to as the tailor-made IV method for closed-loop identification. The indicated equivalence greatly facilitates the understanding and the analysis of the BELS method.

Keywords: System identification; closed-loop identification; prediction error methods; instrumental variables.

1 Introduction

Least squares methods based on the bias-correction principle aim at providing unbiased plant parameter estimates, while using linear-in-the-parameters model structures, see e.g. [2] and [3]. They retain all merits of the LS method and make it possible to cope with the bias problem in the identification of systems subject to colored disturbances. Recently these kind of methods have also been developed for identification under closed-loop conditions [1, 4]. The proposed method, called the bias-eliminated least-squares (BELS) method, is able to estimate unbiased plant parameters in indirect closed-loop system identification. In [5] it has been shown, based on the work of [6], that the bias-eliminated least-squares estimator proposed in [3] for open-loop system identification is identical to a basic instrumental variable estimator. For the closed-loop identification case, the BELS method is analyzed in [7], where a relation is claimed with a particular (and rather complex) frequency weighted IV method, applied to the input and output measurement data, gathered under closed-loop conditions. In [1] the BELS estimate is analyzed for the situation where the order of the controller is not smaller than the order of the open-loop plant. In [4] the method is generalized to avoid this restriction.

In this paper, it will be shown that, whatever the controller order may be, the closed-loop BELS method is equivalent to a so-called tailor-made instrumental variable method, where the predictor for the closed-loop system is used to generate the prediction error and the external reference signals are used as instrumental variables. This connects to the (least squares) tailor-made identification method for closed-loop identification that was recently introduced in the literature, [8, 9]. This equivalence greatly facilitates the understanding and analysis of the BELS method.

2 Preliminaries

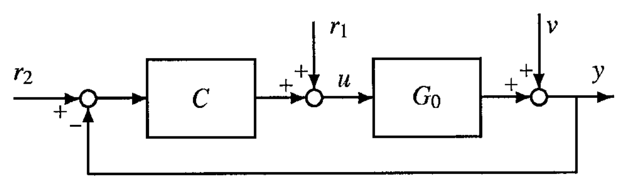


Figure 1: Closed-loop configuration.

Consider a linear SISO closed-loop system shown in figure 1. The process is denoted with $G_0(z)$ and the controller with $C(z)$; $u(t)$ is the process input signal, $y(t)$ the process output signal and $v(t)$ describes the disturbances acting on the loop. The external signals $r_1(t)$, $r_2(t)$ are assumed to be uncorrelated with the noise disturbance $v(t)$. For ease of notation we also introduce the signal $r(t) = r_1(t) + C(q)r_2(t)$. With this notation the closed-loop system can be described as

$$\mathcal{S} : y(t) = \frac{G_0}{1+CG_0} r(t) + \frac{1}{1+CG_0} v(t). \qquad (1)$$

A parametrized process model is considered

$$\mathcal{G}: G(q,\theta) = \frac{B(q^{-1},\theta)}{A(q^{-1},\theta)} = \frac{b_1 q^{-1} + \cdots + b_n q^{-n}}{1 + a_1 q^{-1} + \cdots + a_n q^{-n}} \quad (2)$$

and the process model parameters are stacked columnwise in the parameter vector

$$\theta = \begin{bmatrix} a_1 & \cdots & a_n & b_1 & \cdots & b_n \end{bmatrix}^T \in \mathbb{R}^{2n}. \quad (3)$$

The real plant G_0 is considered to satisfy $G_0(q) = B_0(q^{-1})/A_0(q^{-1})$, while in these expressions q^{-1} is the delay operator, and the numerator and denominator degree is n_0. The m-th order controller C is assumed to be known and specified by

$$C(q) = \frac{Q(q^{-1})}{P(q^{-1})} = \frac{q_0 + q_1 q^{-1} + \cdots + q_m q^{-m}}{1 + p_1 q^{-1} + \cdots + p_m q^{-m}} \quad (4)$$

with the pair (P,Q) assumed to be coprime. The closed-loop transfer function (1) can be rewritten in polynomial fraction form

$$y(t) = \frac{B_{cl}^0}{A_{cl}^0} r(t) + \frac{1}{A_{cl}^0} \xi(t) \quad (5)$$

with $\xi(t) = A_0 P v(t)$. The polynomials B_{cl}^0 and A_{cl}^0 will generically have orders $n_0 + m$.

For parametrizing the closed-loop transfer function $G_0/(1+CG_0)$ the following model structure is used

$$B_{cl}(q^{-1},\Theta) = \beta_1 q^{-1} + \cdots + \beta_{r_B} q^{-r_B} \quad (6)$$

$$A_{cl}(q^{-1},\Theta) = 1 + \alpha_1 q^{-1} + \cdots + \alpha_{n+m} q^{-(n+m)} \quad (7)$$

and the closed-loop parameters are collected in the parameter vector

$$\begin{aligned} \Theta &= \begin{bmatrix} \alpha^T & \beta^T \end{bmatrix}^T \\ &= \begin{bmatrix} \alpha_1 & \cdots & \alpha_{n+m} & \beta_1 & \cdots & \beta_{r_B} \end{bmatrix}^T \in \mathbb{R}^{n+m+r_B}. \end{aligned} \quad (8)$$

For $r_B \geq (n_0 + m)$ the closed-loop model structure will be flexible enough to exactly represent the reference to output transfer function in the closed-loop system (5).

The bias-eliminated least squares method that is considered in this paper attempts to estimate the process parameters by an indirect closed-loop identification. This means that the closed-loop transfer function (5) is identified, after which process parameters (3) are determined.

The relation between (open-loop) process parameters and closed-loop parameters is determined by the linear equation[1]

$$\Theta = M\theta + \rho \quad (9)$$

[1] Note that in [1, 4] the corresponding equation is written as $\Theta = M\theta - \rho$; the difference in sign is due to the fact that in the mentioned references denominator parameters appear with a negative sign in the parameter vectors.

where ρ is a known vector and M is a known full-column rank matrix, given by

$$M = \begin{pmatrix} P_c & Q_c \\ 0 & \bar{P}_c \end{pmatrix} \in \mathbb{R}^{(n+m+r_B)\times 2n} \quad (10)$$

$$\rho = \begin{pmatrix} p_1 & \cdots & p_m & 0 & \cdots & 0 \end{pmatrix}^T \in \mathbb{R}^{(n+m+r_B)} \quad (11)$$

P_c, $Q_c \in \mathbb{R}^{(n+m)\times n}$ are Sylvester matrices expanded by $\begin{bmatrix} 1 & p_1 & \cdots & p_m \end{bmatrix}^T$ and $\begin{bmatrix} q_0 & q_1 & \cdots & q_m \end{bmatrix}^T$ respectively, e.g.

$$P_c = \begin{bmatrix} 1 & 0 & \cdots & 0 \\ p_1 & \ddots & \ddots & \vdots \\ \vdots & \ddots & \ddots & 0 \\ p_m & \vdots & \ddots & 1 \\ 0 & \ddots & \vdots & p_1 \\ \vdots & \ddots & \ddots & \vdots \\ 0 & \cdots & 0 & p_m \end{bmatrix} \quad (12)$$

$\bar{P}_c \in \mathbb{R}^{r_B \times n}$ is also a Sylvester matrix defined by

$$\bar{P}_c = \begin{bmatrix} P_c \\ 0_{(r_B-n-m)\times n} \end{bmatrix}.$$

3 Bias-eliminated least-squares method

The bias-eliminated least-squares method (BELS) for closed-loop identification as discussed in [1, 4] is designed to provide an unbiased estimate for the process model $G(q,\theta)$, while pertaining to simple algorithmic schemes as the linear regression type of estimates. Accurate noise modeling (i.e. finding an noise-shaping filter that models the disturbance signal v) is not considered part of the problem. The method comprises the following main steps:

- Estimate an ARX model for the closed-loop system (5) on the basis of data r and y; this estimate is denoted by $\hat{\Theta}_{ls}$.
- This estimate generally will be biased due to the fact that $\xi(t)$ in (5) will not be white noise; however the bias on $B_{cl}(q^{-1},\hat{\Theta}_{ls})/A_{cl}(q^{-1},\hat{\Theta}_{ls})$ can be estimated and subtracted from the closed-loop estimate;
- The corrected closed-loop parameter is converted to an equivalent open-loop process parameter by solving for (9) in a least squares sense.

In short

$$\text{CL data} \underset{ARX}{\longrightarrow} \hat{\Theta}_{ls} \underset{Computation}{\longrightarrow} \hat{\Theta}_{corr} \underset{LS}{\longrightarrow} \hat{\theta}_{bels}$$

ARX estimate

An ARX estimate for the closed-loop system is obtained through

$$\hat{\Theta}_{ls}(N) = \hat{R}_{\varphi\varphi}(N)^{-1}\hat{R}_{\varphi y}(N)$$

where

$$\hat{R}_{\varphi\varphi}(N) = \frac{1}{N}\sum_{t=1}^{N}\varphi(t)\varphi^T(t) \quad (14)$$

$$\hat{R}_{\varphi y}(N) = \frac{1}{N}\sum_{t=1}^{N}\varphi(t)y(t) \quad (15)$$

$$\varphi(t) = [-y(t-1) \ \cdots \ -y(t-n-m) \ r(t-1) \ \cdots \ r(t-r_B)]^T.$$

Bias correction

The bias correction principle is based on the following reasoning. If the ARX model structure is rich enough to capture all dynamics of the closed-loop system (i.e. if the system is in the model set), then

$$\hat{\Theta}_{ls}(N) = \Theta_0 + \hat{R}_{\varphi\varphi}^{-1}(N)\hat{R}_{\varphi\xi}(N) \quad (16)$$

where Θ_0 is the coefficient vector of the real closed-loop plant, and $\hat{R}_{\varphi\xi}(N) = \frac{1}{N}\sum_{t=1}^{N}\varphi(t)\xi(t)$. Then, under minor regularity conditions on the data, the least squares estimate $\hat{\Theta}_{ls}(N)$ is known to converge for $N \to \infty$ with probability 1 to

$$\Theta_{ls}^* = \Theta_0 + R_{\varphi\varphi}^{-1}R_{\varphi\xi}$$

with $R_{\varphi\varphi} = \bar{E}\varphi(t)\varphi^T(t)$ and $R_{\varphi\xi} = \bar{E}\varphi(t)\xi(t)$, where the notation $\bar{E}[.] = \lim_{N\to\infty}\frac{1}{N}\sum_{t=0}^{N-1}E[.]$ is adopted from the prediction error framework of [10]. As the noise disturbance ξ is assumed to be uncorrelated with the reference signal r, the bias in the asymptotic estimate is given by

$$\Delta^* := R_{\varphi\varphi}^{-1}R_{\varphi\xi} = R_{\varphi\varphi}^{-1}\begin{bmatrix} I_{n+m} \\ 0 \end{bmatrix} R_{y\xi}.$$

with $R_{y\xi} = \bar{E}\{[-y(t-1) \ \cdots \ -y(t-n)]^T \cdot \xi(t)\}$. Based on this expression, an estimate for Δ is obtained by considering

$$\hat{\Delta}(N) := \hat{R}_{\varphi\varphi}^{-1}(N)\begin{bmatrix} I_{n+m} \\ 0 \end{bmatrix}\hat{R}_{y\xi}(N).$$

The unknown $\hat{R}_{y\xi}(N)$ in this relation can be obtained by the following reasoning.

As matrix M in (9) has full column rank, there exists a full column rank matrix $H \in \mathbb{R}^{(n+m+r_B)\times(m+r_B-n)}$ that satisfies $H^T M = 0$. Multiplying equation (16) by H^T and using equation (9) for Θ_0 , it follows that

$$H^T\hat{R}_{\varphi\varphi}^{-1}(N)\begin{bmatrix} I_{n+m} \\ 0 \end{bmatrix}\hat{R}_{y\xi}(N) = H^T(\hat{\Theta}_{ls}(N) - \rho). \quad (17)$$

This is a set of $m+r_B-n$ equations with $n+m$ unknowns in $\hat{R}_{y\xi}(N)$, requiring $r_B \geq 2n$ to have at least as many equations as unknowns. There are two situations to be distinguished

- $m \geq n$ (see [1]). r_B is chosen according to $r_B = n+m$, and equation (17) is an overdetermined set of equations that is solved in least squares sense, leading to

$$\hat{\Delta}(N) = \hat{R}_{\varphi\varphi}^{-1}(N)\begin{bmatrix} I_{n+m} \\ 0 \end{bmatrix}\left[H^T\hat{R}_{\varphi\varphi}^{-1}(N)\begin{bmatrix} I_{n+m} \\ 0 \end{bmatrix}\right]^+ H^T\left[\hat{\Theta}_{ls}(N) - \rho\right] \quad (18)$$

  with $(\cdot)^+$ denoting the matrix pseudo-inverse.

- $m < n$ (see [4]). By choosing $r_B = m+n$ the number of equations in (17) is not sufficient to uniquely determine $\hat{\Delta}$. In [4] this is solved by applying a dynamic prefilter to the reference signal such that effectively a system with higher numerator degree is estimated. This is equivalent to simply choosing $r_B = 2n$, thus obtaining the situation that (17) is uniquely solvable for $\hat{R}_{y\xi}(N)$. An estimate $\hat{\Delta}(N)$ can then be constructed according to

$$\hat{\Delta}(N) = \hat{R}_{\varphi\varphi}^{-1}(N)\begin{bmatrix} I_{n+m} \\ 0 \end{bmatrix}\left[H^T\hat{R}_{\varphi\varphi}^{-1}(N)\begin{bmatrix} I_{n+m} \\ 0 \end{bmatrix}\right]^{-1} H^T\left[\hat{\Theta}_{ls}(N) - \rho\right]. \quad (19)$$

Combining both situations it appears that r_B can be set to $r_B = max(2n, n+m)$. The bias elimination can now be performed by constructing the corrected closed-loop parameter vector

$$\hat{\Theta}_{corr}(N) = \hat{\Theta}_{ls}(N) - \hat{\Delta}(N). \quad (20)$$

Finally the plant parameter estimate $\hat{\theta}_{bels}$ is obtained by solving (9) in a least squares sense

$$\hat{\theta}_{bels}(N) = (M^T M)^{-1}M^T(\hat{\Theta}_{corr}(N) - \rho). \quad (21)$$

It has been shown in [1] and [4] that this resulting parameter estimate is asymptotically unbiased.

4 Tailor-made IV identification

4.1 Main result

In the first step of the BELS method the closed-loop system is estimated with a general ARX (black-box) model structure. However as we know that the closed-loop system has a particular structure (1) with a known controller C, this structure can also be imposed on the parametrization of the closed-loop.

When defining

$$\bar{B}_{cl}(q^{-1},\theta) = B(q^{-1},\theta)P(q^{-1}) \quad (22)$$

$$\bar{A}_{cl}(q^{-1},\theta) = A(q^{-1},\theta)P(q^{-1}) + B(q^{-1},\theta)Q(q^{-1}) \quad (23)$$

a parametrization of the closed-loop system has been obtained, in terms of the process parameters θ. In the literature this is known as a tailor-made parametrization, and has been applied before in prediction error identification with least squares criteria, see e.g. [8] and [9].

Next the main result is formulated.

Proposition 1 *Consider a data generating system according to (1), such that the closed-loop system is asymptotically stable, and consider the BELS estimate $\hat{\theta}_{bels}(N)$ given by (21), with $r_B = max(2n, n+m)$, and r persistently exciting of sufficiently high order.*

Define the weighted tailor-made IV estimate $\hat{\theta}_{iv,F}(N)$ as the solution to the set of $2n$ equations

$$\frac{1}{N}\sum_{t=1}^{N}\varepsilon(t,\hat{\theta}_{iv,F})\eta(t) = 0 \tag{24}$$

$$\varepsilon(t,\theta) = \bar{A}_{cl}(q^{-1},\theta)y(t) - \bar{B}_{cl}(q^{-1},\theta)r(t) \tag{25}$$

$$\eta(t) := F\varphi_r(t), \quad F \in \mathbb{R}^{2n\times r_B} \tag{26}$$

$$\text{with } \varphi_r(t) = \begin{bmatrix} r(t-1) & \cdots & r(t-r_B)\end{bmatrix}^T \in \mathbb{R}^{r_B} \tag{27}$$

with

$F = I_{2n}$ *in the situation* $m \leq n$, *and*

$F = M^T\hat{R}^T_{\varphi_r\varphi}(\hat{R}_{\varphi_r\varphi}\hat{R}^T_{\varphi_r\varphi})^{-1}$ *in the situation* $m > n$.

Then

$$\hat{\theta}_{bels}(N) = \hat{\theta}_{iv,F}(N).$$

Proof. A full proof can be found in [11].

Remarks.

- If the order of the process model exceeds the controller order ($n \geq m$), the parameter estimate is a simple tailor-made IV estimate, where the closed-loop prediction error is made orthogonal to delayed versions of the external reference signal. Related estimation algorithms based on a least squares criterion $\sum_t \varepsilon^2(t,\theta)$ have been considered in [8] and [9]. The indicated equivalence greatly facilitates the understanding and analysis of the BELS-estimator. Moreover, it also allows the analysis of the estimator under conditions where the real process is not considered to be present in the model set. Note that in the formulation of the main result it is *not* assumed that G_0 has order n.
- In the situation $m < n$, it is suggested by [4] to introduce an auxiliary filter operating on the reference signals in order to increase the number of numerator parameters to identify. Here it is shown, as was also indicated by [7], that this dynamic prefilter is superfluous. The problem can be handled by simply choosing $r_B = 2n$, i.e. by deliberately enlarging the number of numerator parameters to estimate.
- When $m > n$, the estimator is obtained by using a linear combination of delayed samples of the reference signal, to act as an instruments in the IV estimator.
- In this paper we have dealt with strictly proper plant models, having at least one time-delay ($b_0 = 0$). The situation of proper plant models in the BELS estimate is completely similar with appropriate adaptation of matrix and vector dimensions, provided that in the closed loop there is at least one time-delay, i.e. $b_0q_0 = 0$. The tailor-made IV method does not require the presence of such a loop delay.
- A relation with other works can be found in [11].

4.2 Interpretation of matrix F

In order to interpret the role of matrix F, let us analyse $\varepsilon(t,\hat{\theta}_{bels})$, the equation error of the BELS estimator. As the connection between IV and BELS estimators has been stated, the equation error can be written as

$$\varepsilon(t,\hat{\theta}_{iv,F}) = y(t) - \varphi^T(t)(M\hat{\theta}_{iv,F} + \rho). \tag{28}$$

This equation can be simplified by analyzing the constituting expressions. At first, it can be noticed that the controller denominator $P(q^{-1})$ can be used as a prefilter for the output $y(t)$. Then, with

$$\bar{y}(t) = P(q^{-1})y(t) \tag{29}$$

it follows that

$$\bar{y}(t) = y(t) - \varphi^T(t)\rho \tag{30}$$

The second expression $\varphi^T(t)M$ can be rephrased by considering the plant description

$$y(t) = \psi^T(t)\theta_0 + A_0(q^{-1})v(t),$$

with

$$\psi(t) = [-y(t-1) \cdots -y(t-n) \\ u(t-1) \cdots u(t-n)]^T \in \mathbb{R}^{2n}.$$

In a filtered version this reads:

$$\bar{y}(t) = \bar{\psi}^T(t)\theta_0 + P(q^{-1})A_0(q^{-1})v(t) \tag{31}$$

where $\bar{\psi}(t) := P(q^{-1})\psi(t)$. Similarly,

$$y(t) = \varphi^T(t)(M\theta_0 + \rho) + P(q^{-1})A_0(q^{-1})v(t)$$

leading to

$$\bar{y}(t) = \varphi^T(t)M\theta_0 + P(q^{-1})A_0(q^{-1})v(t)$$

which combined with (31) shows that

$$\bar{\psi}^T(t) = \varphi^T(t)M.$$

Using this expression in (28) leads to

$$\varepsilon(t,\hat{\theta}_{iv,F}) = \bar{y}(t) - \bar{\psi}^T(t)\hat{\theta}_{iv,F}. \quad (32)$$

For a further interpretation two cases have to be considered, according to the orders of the controller and the system.

Case $m \leq n$.

If the controller order is smaller than or equal to the system order, it has been stated that F is equal to the identity matrix and the tailor-made IV estimate satisfies

$$\hat{R}_{\varphi_r\varepsilon} = 0. \quad (33)$$

By substituting (32) in (33), this yields

$$\hat{R}_{\varphi_r\bar{y}} - \hat{R}_{\varphi_r\bar{\psi}}\hat{\theta}_{iv,F} = 0. \quad (34)$$

If the signal $r(t)$ is persistently exciting, of sufficient order, the squared matrix $\hat{R}_{\varphi_r\bar{\psi}} \in \mathbb{R}^{2n\times 2n}$ is invertible and thus the IV estimate is given by

$$\hat{\theta}_{iv} = \hat{R}^{-1}_{\varphi_r\bar{\psi}}\hat{R}_{\varphi_r\bar{y}}. \quad (35)$$

Case $m > n$.

In the case where the controller order is greater than the system order, the vector φ_r is made up of $(n+m)$ components (see the proposition). It follows that the matrix $\hat{R}_{\varphi_r\bar{\psi}} \in \mathbb{R}^{(n+m)\times 2n}$ is not invertible. Thus, the matrix F is added in order to make it invertible, i.e. to make $\hat{R}_{\varphi_r\bar{\psi}}$ regular. In this case, F is equal to $M^T\hat{R}^T_{\varphi_r\varphi}(\hat{R}_{\varphi_r\varphi}\hat{R}^T_{\varphi_r\varphi})^{-1}$ and the tailor-made IV estimate satisfies

$$\hat{R}_{F\varphi_r\varepsilon} = 0. \quad (36)$$

By substituting (32) in (36), it follows

$$\hat{R}_{F\varphi_r\bar{y}} - \hat{R}_{F\varphi_r\bar{\psi}}\hat{\theta}_{iv,F} = 0. \quad (37)$$

If $r(t)$ is persistently exciting of sufficient order, the matrix $\hat{R}_{F\varphi_r\bar{\psi}} \in \mathbb{R}^{2n\times 2n}$ is invertible and the IV estimate can be written as

$$\hat{\theta}_{iv} = \hat{R}^{-1}_{F\varphi_r\bar{\psi}}\hat{R}_{F\varphi_r\bar{y}}. \quad (38)$$

The matrix $\hat{R}_{F\varphi_r\bar{\psi}}$ can be regarded as the product of two matrices F and $\hat{R}_{\varphi_r\bar{\psi}}$. $F \in \mathbb{R}^{2n\times(n+m)}$ and $\hat{R}_{\varphi_r\bar{\psi}} \in \mathbb{R}^{(n+m)\times 2n}$ have both rank $2n$. Thus, the product $F\hat{R}_{\varphi_r\bar{\psi}}$, or equivalently $\hat{R}_{F\varphi_r\bar{\psi}}$, is squared (dimensions $2n \times 2n$) and has rank $2n$.

5 Simulation example

Consider the process and controller given in [4] and described by the following transfer functions:

$$G(q^{-1}) = \frac{B(q^{-1})}{A(q^{-1})} = \frac{q^{-1}+0.5q^{-2}}{1-1.85q^{-1}+0.525q^{-2}}, \quad (39)$$

$$C(q^{-1}) = \frac{Q(q^{-1})}{P(q^{-1})} = \frac{0.35-0.28q^{-1}}{1-0.8q^{-1}}. \quad (40)$$

The closed-loop system is then described by:

$$B_{cl}(q^{-1}) = q^{-1} - 0.3q^{-2} - 0.4q^{-3} \quad (41)$$

$$A_{cl}(q^{-1}) = 1 - 2.3q^{-1} + 1.9q^{-2} - 0.56q^{-3} \quad (42)$$

$$y(t) = y_d(t) + y_n(t) \quad (43)$$

$$= \frac{B_{cl}(q^{-1})}{A_{cl}(q^{-1})}r(t) + \frac{A(q^{-1})P(q^{-1})}{A_{cl}(q^{-1})}e(t), \quad (44)$$

with $e(t)$ and $r(t)$ white noises uncorrelated. Note that the process is unstable and the closed-loop transfer function is overparametrised by a common factor $1-0.8q^{-1}$. Process parameters are estimated on the basis of closed-loop data sequences of length $N = 1000$. Monte Carlo simulations of 200 experiments have been performed for two different signal to noise ratios:

$$SNR = 10\log\left(\frac{\sigma^2_{y_d}}{\sigma^2_e}\right) = 10,\ 30\ \text{dB}, \quad (45)$$

where σ denotes the standard deviation. The process parameters obtained by the tailor instrumental variable (tailorIV) are calculated, and for illustration purposes they are compared with estimates obtained by the optimal instrumental variable (IV4) method [10]. The results are given in tables 1 and 2. The standard deviations (std) are also presented.

	b_1	b_2	a_1	a_2
θ_0	1	0.5	-1.85	0.525
tailorIV	1.000	0.500	-1.850	0.525
std	0.019	0.026	0.025	0.036
IV4	0.989	0.502	-1.851	0.526
std	0.046	0.024	0.029	0.014

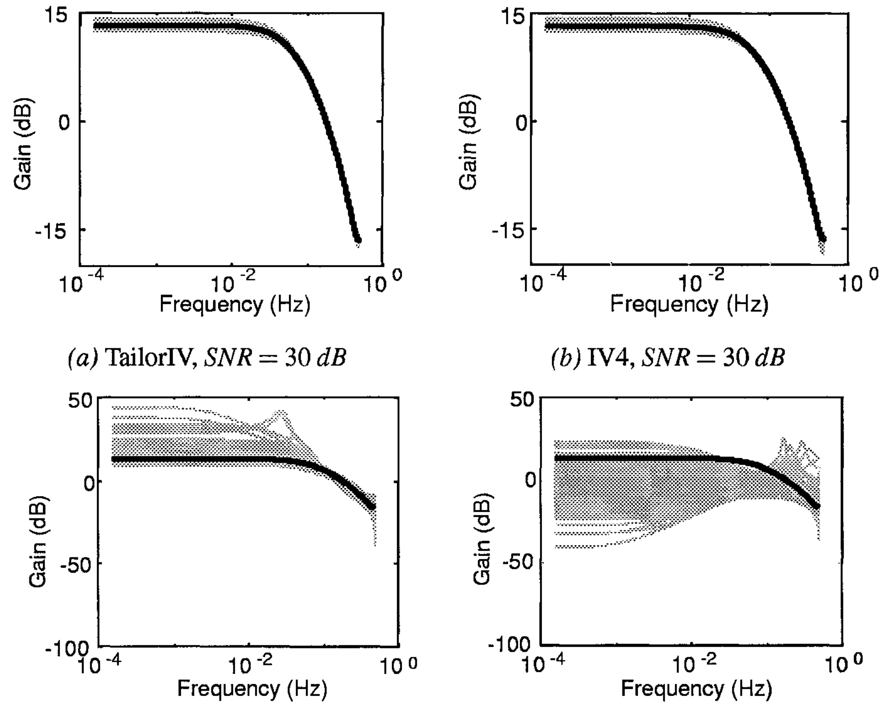
Table 1: Plant parameter estimates for $SNR = 30dB$

	b_1	b_2	a_1	a_2
θ_0	1	0.5	-1.85	0.525
tailorIV	1.006	0.480	-1.864	0.553
std	0.193	0.233	0.209	0.329
IV4	0.065	0.543	-1.559	0.409
std	0.562	0.360	0.761	0.133

Table 2: Plant parameter estimates for $SNR = 10dB$

Figure 2 represents the Bode diagrams of the 200 models identified by the two previous methods and for two signal to noise ratios (10 and 30 dB).

Whereas the tailor-made IV method leads to asymptotically unbiased results, the IV4 estimates are biased due to the fact that the plant input signal is corrupted by noise (and so is the simulated output signal which is used as a basis for the instruments). This situation becomes more apparent under high noise disturbances. The tailorIV method gives good results in both low-noise and high-noise situations, although in the latter situation the variance error becomes dominant. Figures 2(c) and 2(d) show that for the tailorIV method the variance error is dominating in the low-frequency range, while for the IV4 method the variance error is more substantial in the high-frequency region.



(a) TailorIV, $SNR = 30\ dB$ (b) IV4, $SNR = 30\ dB$

(c) TailorIV, $SNR = 10\ dB$ (d) IV4, $SNR = 10\ dB$

Figure 2: Bode diagrams of the process (black) and of the estimates (grey), $SNR = 30,\ 10\ dB$

6 Conclusions

It has been shown that a bias-eliminated least-squares (BELS) estimator for closed-loop identification is equivalent to an instrumental variable estimator, where the predictor considered reflects the closed-loop system, and where external reference signals act as instrumental variables. This requires a tailor-made parametrization of the closed-loop system, as has been used in the literature before in a least squares setting. The relation between BELS and IV greatly facilitates the understanding and analysis of the former method.

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