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STRUCTURAL TIME DOMAIN IDENTIFICATION TOOLBOX
USER'S GUIDE
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Introduction

1 Introduction

This manual describes the Structural Time Domain Identification toolbox for use with MATLAB. This version of the toolbox has been developed using the PC-based MATLAB version 4.2c, but is compatible with prior versions of MATLAB and UNIX-based versions. The routines of the toolbox are the so-called m-files that can be executed from the MATLAB command prompt or built into other m-files.

The primary purpose of the toolbox is system identification of stochastic excited linear and time-invariant systems. In some cases though, it is possible to include measured excitation into the identification process as well. One of the primary results of the system identification is the estimation of modal parameters. In this toolbox the estimated modal parameters are the natural eigenfrequencies, the damping ratios and the scaled complex mode shapes. The identification of these parameters can be obtained by different identification techniques.

1.1 State Space Representation

The identification of the modal parameters can be based on the calibration of a state space system on the basis of measurements. In case of ambient excited structures only the system response will be available. In this case the dynamic behaviour of a linear and time-invariant system subjected to stationary ambient excitation can be modelled by the following system

\[ x(t_{i+1}) = Ax(t_i) + Ke(t_i), \quad e(t_i) \sim \text{NID}(0, \Lambda) \]
\[ y(t_i) = Cx(t_i) + e(t_i) \]

where the dimensions and the parameters of the matrices \( A, C \) and \( K \), together with the innovations \( e(t_i) \), are adjusted in order to describe the measured system response \( y(t_i) \) optimally.

1.2 ARMAV Representation

The innovation system can also be represented in polynomial form by the so-called Auto-Regressive Moving Average Vector model

\[ y(t_i) = A_1y(t_{i-1}) + \ldots + A_py(t_{i-p}) + \]
\[ e(t_i) = C_1e(t_{i-1}) + \ldots + C_pe(t_{i-p}), \quad e(t_i) \sim \text{NID}(0, \Lambda) \]

In this case, the auto-regressive coefficient matrices and the moving average coefficient matrices, together with the innovations \( e(t_i) \), are adjusted in order to describe the measured system response \( y(t_i) \) optimally.

The innovation state space system and the ARMAV model are equivalent descriptions of a stationary excited linear and time-invariant system. For a \( p \)-variate system the relation between the state space dimension \( m \) and the order \( n \) of the ARMAV model is \( np = m \).
1.3 Modal Parameter Estimation

The modal parameters of a linear and time-invariant system are obtained by a modal decomposition of the transition matrix $A$

$$\Psi^{-1} A \Psi = \mu, \quad \mu = \text{diag} \{ \mu_j \} \quad j = 1, 2, \ldots, m$$

where $\Psi$ is the complex modal matrix, whose columns are the eigenvectors of the transition matrix. $\mu$ is a diagonal matrix of associated eigenvalues. The complex mode shapes are extracted from the complex modal matrix as

$$\Phi = C \Psi$$

where $\Phi$ is a matrix, whose columns are the scaled complex mode shapes. By means of the sampling interval $T$, the natural eigenfrequencies $f_j$ and the damping ratios $\zeta_j$ are extracted from the discrete-time eigenvalues $\mu_j$ of the underdamped structural modes as

$$\lambda_j = \frac{\log (\mu_j)}{T}$$

$$f_j = \frac{|\lambda_j|}{2 \pi}$$

$$\zeta_j = -\frac{\text{Re} (\lambda_j)}{|\lambda_j|}$$

If the identified system is described by an ARMAV model this model is converted into state space before the modal decomposition is performed.

1.4 Organizing the Results

One of the most important problems that must be solved by a good system identification software is, how to organize all the results that are generated through a system identification session. In this context, it is important to distinguish between primary and secondary results. Primary results are defined as results obtained directly from an identification algorithm. These results will typically be:

- Model structure information.
- Estimated model parameters.
- Estimated uncertainties of the model parameters.
- Estimated innovation covariance matrix.
- Performance criteria.

The model structure information will typically be a set of parameters describing the dimensions of the identified model, and which of the parameters of the model have been estimated and which of them have been held constant. Other primary results are the estimated uncertainties of the estimated model parameters. These uncertainties are based upon the Hessian of the criterion.
function and must therefore be estimated inside the identification algorithm. This also accounts for the estimated innovation covariance matrix, which is based upon the prediction errors calculated from the final parameter estimates and the measurements, and the performance measures such as the AIC and FPE criteria. Based on these primary results any secondary result can be calculated.

Typical secondary results are the modal parameters and the spectral densities of the response of the model. The decisions about whether the model is optimal or not can also be characterized as a secondary result, since this decision is based on analysis of different primary results. Common to all secondary results is that they can be calculated at any time if the primary results are available. It is therefore unnecessary to store these results. In the toolbox the storage of the primary results is performed by organizing these in one matrix structure, which is called a DDS structure matrix. DDS is an abbreviation of Data Dependent Systems which is a synonym for system identification based on measured data. The content of this matrix is presented in table 1.1.

<table>
<thead>
<tr>
<th>The DDS Structure Matrix</th>
</tr>
</thead>
<tbody>
<tr>
<td>Model structure information</td>
</tr>
<tr>
<td>Index of adjustable parameters</td>
</tr>
<tr>
<td>Adjustable and non-adjustable model parameters</td>
</tr>
<tr>
<td>Estimated covariance matrix of adjustable model parameters</td>
</tr>
<tr>
<td>Estimated innovation covariance matrix</td>
</tr>
<tr>
<td>Number of measurements channels</td>
</tr>
<tr>
<td>Number of measurements in each channel</td>
</tr>
<tr>
<td>Scaling matrix of the measurements</td>
</tr>
<tr>
<td>Sampling interval</td>
</tr>
<tr>
<td>Final loss (Final value of the criterion function)</td>
</tr>
<tr>
<td>Akaike's Final Prediction Error Criterion (FPE)</td>
</tr>
<tr>
<td>ID number for the routine that created the structure</td>
</tr>
<tr>
<td>Time and date for the creation of the structure</td>
</tr>
</tbody>
</table>

Table 1.1: Information stored in the DDS structure matrix.

The creation of the structure is performed automatically by the identification routines, and the access to the different elements of the structure is provided by different functions. A call to an identification routine in the MATLAB environment will typically look like

```matlab
dds = function(y, ddsinit)
```

where `y` is the measured output and `ddsinit` is an initial DDS structure containing initial model parameters and model structure information. The primary results of the identification are then returned in `dds`. On the basis of the primary results stored in `dds` the model validation routines are typically called by

```matlab
valid_result = function(dds, y)
```

and secondary results, such as the modal parameters, are typically obtained by

```matlab
second_result = function(dds)
```
2 An Introductory Example

The best way to introduce the toolbox is by considering an example. The following example is an edited version of the demonstration m-file demostdi.m located in the toolbox. This file can be executed from the MATLAB command line prompt as

```matlab
* demostdi
```

2.1 Simulating System Response

This file demonstrates some of the routines of the toolbox. In order to generate some response of some system, a continuous-time Gaussian white noise excited 3 degree-of-freedom system is constructed.

The system is described by the following stiffness matrix $K$, viscous (non-proportional) damping matrix $C$, and mass matrix $M$.

$$
K = \begin{bmatrix}
350 & -150 & 0 \\
-150 & 450 & -300 \\
0 & -300 & 400 \\
\end{bmatrix}
$$

$$
C = \begin{bmatrix}
0.7000 & -0.2000 & 0 \\
-0.2000 & 0.4000 & -0.2000 \\
0 & -0.2000 & 0.8000 \\
\end{bmatrix}
$$

$$
M = \begin{bmatrix}
1 & 0 & 0 \\
0 & 1 & 0 \\
0 & 0 & 1 \\
\end{bmatrix}
$$

The continuous-time Gaussian white noise excitation is described by the intensity matrix $W$ given by

$$
W = \begin{bmatrix}
2 & 0 & 0 \\
0 & 2 & 0 \\
0 & 0 & 2 \\
\end{bmatrix}
$$

On the basis of this information a covariance equivalent discrete-time ARMA$(2,1)$ model can be established. The simulated samples of the response obtained from such a model has the correct statistical properties in case of Gaussian distributed continuous-time system response.

The conversion to discrete time is performed by the following command line call:

```matlab
* T=0.075; 
* dds=armav21(M,C,K,T,W); 
```

where $T$ is the sampling interval. The structure matrix $dds$ contains all the necessary primary information about the constructed ARMA model. This information can be furnished to the screen using the command line call:

```matlab
* showdds(dds); 
```
The output from this call is the following information:

This discrete-time 3-channel ARMAV(2,1) model was created by the command ARMAV21 on the 24/9 1997 at 09:46.
It was based on 0 samples in each channel, and a sampling interval of 0.075 seconds.
Loss function: 0, Akaike FPE: 0

The parameters and their standard deviations given as imaginary parts are:

A =
Columns 1 through 7
1 0 0 -0.3769 -0.5539 -0.1014 0.9486
0 1 0 -0.5630 -0.1967 -1.0919 0.0118
0 0 1 -0.0973 -1.0737 -0.3301 0.0003

Columns 8 through 9
0.0177 -0.0020
0.9726 0.0087
0.0201 0.9403

C =
1 0 0 0 0.3401 -0.0350 0.0034
0 1 0 -0.0378 0.3752 -0.0774
0 0 1 0.0045 -0.0721 0.3581

The innovation covariance matrix is:

Lam =
1.0e-003 *
0.3283 0.0652 0.0114
0.0652 0.3167 0.1217
0.0114 0.1217 0.3214

The scaling matrix of the response is:

Scale =
1 0 0
0 1 0
0 0 1

The system response can now be simulated using the following command line call:

```
• p=3;
• N=3000;
• y=ddssim(dds,randn(N,p));
```

The number of simulation in each of the three outputs is 3000. Noise can then be added in order to simulate real measurements even more:

```
• y=y+0.1*mean(std(y))'*randn(N,p);
```

The added noise is zero-mean Gaussian white noise with a standard deviation equal to 10 per cent of the averaged standard deviations of the noise-free simulations.
An Introductory Example

2.2 Model Estimation

The modal parameters of the simulated system can then be estimated from the measurements by the estimation of an adequate ARMAV(2,2) model. The estimation will be based on the Prediction Error Method. This method requires a good initial estimate which can be provided by the stochastic subspace ARMA estimator. This estimator can be invoked by the following command line call:

```matlab
> ddsinit=armavnn(y,20,2,T);
```

Again the information stored in ddsinit can be viewed:

```matlab
> showdds(ddsinit);
```

This discrete-time 3-channel ARMAV(2,2) model was created by the command ARMAVNN on the 24/9 1997 at 09:52.

It was based on 3000 samples in each channel, and a sampling interval of 0.075 seconds.

Loss function: 0.0000937, Akaikes FPE: 0.00009597

The parameters and their standard deviations given as imaginary parts are:

A =

<table>
<thead>
<tr>
<th>Column 1 through 7</th>
<th>Column 8 through 9</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0.0293 -0.0081</td>
</tr>
<tr>
<td>0</td>
<td>0.9654 0.0100</td>
</tr>
<tr>
<td>0</td>
<td>0.0165 0.9478</td>
</tr>
</tbody>
</table>

C =

<table>
<thead>
<tr>
<th>Column 1 through 7</th>
<th>Column 8 through 9</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>-0.0958 0.0072</td>
</tr>
<tr>
<td>0</td>
<td>0.2391 -0.0805</td>
</tr>
<tr>
<td>0</td>
<td>-0.0971 0.2178</td>
</tr>
</tbody>
</table>

The innovation covariance matrix is:

<table>
<thead>
<tr>
<th>Lam</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0721 0.0124 0.0049</td>
</tr>
<tr>
<td>0.0124 0.0383 0.0147</td>
</tr>
<tr>
<td>0.0049 0.0147 0.0416</td>
</tr>
</tbody>
</table>

The scaling matrix of the response is:

<table>
<thead>
<tr>
<th>Scale</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.0953 0.1355 0.1304</td>
</tr>
<tr>
<td>0 0 0</td>
</tr>
<tr>
<td>0 0 0</td>
</tr>
</tbody>
</table>

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2-3
An Introductory Example

Based on this initial model information as well as on the system response the Prediction Error Method can be used to iteratively improve the estimate of the state space system. The prediction error method for ARMAV models is applied in the following manner:

* `ddsarmav=armav(y,ddsinit);`

This routine will then iteratively reduce the prediction errors of the model. In other words, the differences between the measurements and the system response predicted by the estimated model.

2.3 Model Validation

One way to validate the performance of the ARMAV model is to compare the spectral densities obtained from the model and from FFT. Such comparative plots are obtained from the command line call:

* `speccmp(ddsarmav,y);`

An example of such a plot is shown below.

![Example plot]

2.3 Modal Parameter Estimation

Assuming that the performance of the estimated model is satisfactory the modal parameters can be estimated. This can be accomplished by the following command line call:

* `[phi,f,z]=modal(ddsarmav,1);`

with `phi` being a matrix whose columns are the scaled complex mode shapes. `f`, `z` are vectors of associated natural eigenfrequencies and damping ratios.
An Introductory Example

These modal parameters can be compared with the ones of the simulation system by the following command line calls:

```matlab
> [phi0,f0,z0]=modal(dds,1);
> disp(phi0);
0.5934 + 0.0041i -1.9207 + 0.0194i 0.4387 + 0.0052i
1.0583 + 0.0078i 0.1322 + 0.0027i -1.1905 + 0.0184i
1.0000 1.0000 1.0000
> disp(phi1)
0.5948 + 0.0039i -1.9402 + 0.0442i 0.4337 + 0.0160i
1.0626 + 0.0071i 0.1252 + 0.0025i -1.1951 + 0.0103i
1.0000 1.0000 1.0000
> disp([f0 100*z0])
1.4454 1.8261
3.0211 1.0241
4.3794 1.5225
> disp([f1 100*z])
[f 100*z] =
1.4508 1.7884
3.0246 1.7607
4.3818 1.6321
```

which reveal a good correspondence of all estimated and simulated modal parameters.
3 Installation

This toolbox is installed by copying the files of the installation disk to the hard disk. We recommend that the files are installed in the MATLAB directory and that the installation directory is named stdi. Afterwards this directory must be added to the MATLAB search path by editing the m-file matlabrc.m located in the MATLAB directory.

Having installed the toolbox correctly it should be possible to execute the routine initstdi. This routine initializes the default parameters used by the routines of the toolbox. Further, it configures the font size of the graphical plotting facilities of the toolbox. All settings are saved in the file stdi.mat which must be located in a directory present in the MATLAB search path. If the routine is not called initially, a default stdi.mat will be generated automatically. The values of the stdi.mat file can always be edited by calling initstdi.

initstdi is a menu-driven routine and is easy to use. The following options are available:

1. Retrieve Default Configuration
2. Edit Plot and Axis Font Sizes
3. Edit PEM Optimization Parameters
4. Edit Sampling Interval
H. Help
S. Save and Quit
Q. Quit

The default configuration (1) sets all parameters and font sizes to default values. The font sizes can be edited by the option (2). The algorithms implementing the prediction error method for different model structures also need to be configured which is performed by the option (3). If a particular sampling interval is used frequently this can be set by the option (4). Help is provided by the option (H) and the configuration is saved using option (S). After saving the routine quits. This can also be accomplished without saving using option (Q).
This section contains detailed descriptions of all the functions in the Structural Time Domain Identification Toolbox. It begins with a list of functions grouped by a subject area and continues with the Reference entries in alphabetical order. Information is also available through the online Help facility.

For ease of use, most functions have several default arguments. The Synopsis first lists the function with the necessary input arguments and then with all possible input arguments. The functions can be used with any number of arguments in between these extremes. The rule is that missing, trailing arguments are given default values, as defined in the manual or by the routine initstdi. Default values are also obtained by entering the arguments as the empty matrix [ ].

MATLAB does not require that you specify all the output arguments; those not specified are not returned. For functions with several output arguments in the Structural Time Domain Identification Toolbox, missing arguments are, as a rule, not computed, in order to save time.

<table>
<thead>
<tr>
<th>Non-parametric estimation</th>
</tr>
</thead>
<tbody>
<tr>
<td>fftcor</td>
</tr>
<tr>
<td>fftcov</td>
</tr>
<tr>
<td>fftspec</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Parameter Estimation</th>
</tr>
</thead>
<tbody>
<tr>
<td>arv</td>
</tr>
<tr>
<td>arnarmav</td>
</tr>
<tr>
<td>armavnn</td>
</tr>
<tr>
<td>armavgls</td>
</tr>
<tr>
<td>na4sid</td>
</tr>
<tr>
<td>sspem</td>
</tr>
<tr>
<td>initpem</td>
</tr>
</tbody>
</table>

Correlation function estimate for a data matrix.
Covariance function estimate for a data matrix.
Power spectrum estimation of a data matrix.
ARV models of signals using a least-squares approach.
ARMAV models of signals using the Prediction Error Method.
ARMAV models of signals using the stochastic subspace technique
ARMAV models of signals using a generalized least-squares approach.
Estimation of a stochastic state space realization of signals using the stochastic subspace technique.
Estimation of a stochastic state space realization of signals using the Prediction Error Method.
Generate initial information for sspem.
### Simulation and Prediction

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>dds2pe</td>
<td>Computes the prediction errors of an estimated model.</td>
</tr>
<tr>
<td>dds2pred</td>
<td>Computes the one-step ahead prediction of an estimated model.</td>
</tr>
<tr>
<td>ddssim</td>
<td>Simulates the response of a model.</td>
</tr>
</tbody>
</table>

### Model Structure Creation

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>armav21</td>
<td>DDS structure of a covariance equivalent ARMAV(2,1) model.</td>
</tr>
<tr>
<td>mck2dds</td>
<td>DDS structure of a second-order continuous-time system.</td>
</tr>
<tr>
<td>par2dds</td>
<td>DDS structure created from matrix polynomial parameters.</td>
</tr>
<tr>
<td>poly2dds</td>
<td>DDS structure from given matrix polynomials.</td>
</tr>
<tr>
<td>ss2dds</td>
<td>DDS structure of a given state space realization.</td>
</tr>
</tbody>
</table>

### Model Conversions

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>dds2cov</td>
<td>Covariance function of a linear system excited by Gaussian white noise.</td>
</tr>
<tr>
<td>dds2frf</td>
<td>Frequency response function and noise spectral densities.</td>
</tr>
<tr>
<td>dds2par</td>
<td>Parameters of the model contained in the DDS structure.</td>
</tr>
<tr>
<td>dds2poly</td>
<td>Computes the matrix polynomials associated with a given model.</td>
</tr>
<tr>
<td>dds2ss</td>
<td>Converts the DDS structure to a state space realization.</td>
</tr>
<tr>
<td>modal</td>
<td>Modal decomposition of a model.</td>
</tr>
</tbody>
</table>

### Model Presentation

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>dds2spec</td>
<td>Plots frequency response functions and noise spectral densities.</td>
</tr>
<tr>
<td>showdds</td>
<td>Furnishes information about the model to the screen.</td>
</tr>
<tr>
<td>Reference</td>
<td>Reference</td>
</tr>
<tr>
<td>-----------</td>
<td>-----------</td>
</tr>
<tr>
<td><strong>Model Validation</strong></td>
<td><strong>Manipulating Model Structures</strong></td>
</tr>
<tr>
<td>dds2pe</td>
<td>dd2dds</td>
</tr>
<tr>
<td>dds2pred</td>
<td>dds2idds</td>
</tr>
<tr>
<td>specamp</td>
<td><strong>Information Extraction</strong></td>
</tr>
<tr>
<td><strong>Assessing Model Uncertainty</strong></td>
<td></td>
</tr>
<tr>
<td>dds2par</td>
<td>Covariance matrix of estimated parameters.</td>
</tr>
<tr>
<td>sdmodal</td>
<td>Estimated uncertainties of the modal parameters.</td>
</tr>
</tbody>
</table>

| **Information Extraction** | **Assessing Model Uncertainty** |
| dds2id | System identification information from a model. |
| dds2t | Returns the sampling interval on which a model is based. |
| dim/dimss | Dimensions of the model and the number of channels. |
| modal | Modal parameters of the model. |
| isdds | Checks if a matrix is an DDS structure. |
| isddscs | Checks if an DDS structure contains a continuous-time model. |
| isddsss | Checks if an DDS structure contains a state space realization. |

| RMAV(2,1) | Manipulating Model Structures |
| -time sys- | t2dds | \( \text{Set sampling interval.} \) |
| -ial parame- | dds2idds | \( \text{Internal conversion of the DDS structure.} \) |
| -ls. | **Information Extraction** |
| **Assessing Model Uncertainty** |
| dds2par | Covariance matrix of estimated parameters. |
| sdmodal | Estimated uncertainties of the modal parameters. |

n Toolbox User's Guide

Structural Time Domain Identification Toolbox User's Guide

4-3
Purpose

ARMAV models of signals using the Prediction Error Method.

Synopsis

dds=armav(y,NN)
dds=armav(y,NN,maxiter,tol,maxsize,T,lim,nocovar,noscale,app)

Description

The parameters of the full polynomial ARMAV model structure

\[ A(q)y(t) = C(q)e(t) \]

are estimated using a prediction error method [1].

\( y \) is a matrix with the time series data of each channel stored columnwise. \( NN \) contains initial value and structure information. The dds structure matrix is returned with the resulting parameter estimates, together with estimated covariance matrices. When no initial parameter estimates are available, enter \( NN=[na,nc] \), the orders of the above model. With an initial estimate available in ddsinit, a DDS structure matrix of standard format, enter \( NN=ddsinit \). Then the criterion minimization is initialized at ddsinit.

The optional argument \( app \) is a string that controls the search-scheme to use. If \( app='GN' \) a Gauss-Newton search-scheme is applied. If \( app='ML' \) the search-scheme will be of the Marquardt-Levenberg type. The optional auxiliary arguments maxiter, tol, maxsize, T, nocovar and noscale are explained under auxlsvar.

Algorithm

If \( approach='GN' \) a robustified quadratic prediction error criterion is minimized using an iterative damped Gauss-Newton algorithm. The Gauss-Newton vector is bisected up to ten times until a lower value of the criterion function is found. The iterations are terminated when maxiter is reached, when the Gauss-Newton search gradient has a norm less than tol, or when a lower value of the criterion cannot be found.

If \( approach='ML' \) the same robustified quadratic prediction error criterion is minimized using an iterative Marquardt-Levenberg algorithm. The iterations are terminated when maxiter is reached, when the Marquardt-Levenberg search gradient vector has a norm less than tol, or when a lower value of the criterion cannot be found.

In order to obtain an initial guess of the parameters an initialization using a two-stage linear least-squares algorithm is used. This initialization is allowed to use ten iterations before terminating.
The cutoff value for the robustification is based on the parameter \( \text{lim} \) as well as on the estimated standard deviation of the residuals from the current parameter estimate. The returned loss function and innovation covariance matrix are the non-robustified ones.

A stability test of the predictor is performed, so as to assure that only models corresponding to stable predictors are tested. Generally, the moving average matrix polynomial must have all its roots inside the unit circle.

Information about the minimization is furnished to the screen. Currently estimated parameters as well as values of the current and previous criterion functions are given. The norm of either the Gauss-Newton or the Marquardt-Levenberg search gradient is also displayed. If configured for it, a graphical PEM Information Window will appear and present the information as well. This is controlled by the routine initstdi.

If configured for it, the routine will save all information about the identification after each iteration. In this way the currently obtained results are saved if a breakdown of the system should occur or if CRTL-C is hit. This is controlled by the routine initstdi. If the routine is stopped before completion, the data can be restored by the routine tmp2dds.

See Also
armavnn, armavgls, sspe, auxlsvar, ddsstruc, tmp2dds, initstdi

Reference

**armav21**

**Purpose**

Generate a discrete-time covariance equivalent ARMAV model of a continuous-time second order linear system excited by Gaussian white noise.

**Synopsis**

```matlab
dds = armav21(M, C, K, T)
dds = armav21(M, C, K, T, W, disp)
```

**Description**

The parameters of the $p$-variate ARMAV(2,1) model structure

$$A(q)y(t) = C(q)e(t)$$

are calculated on the basis of equivalence of the covariance function of the linear continuous-time time-invariant Gaussian white noise excited system, described by the differential equation

$$M\ddot{y}(t) + C\dot{y}(t) + Ky(t) = w(t), \quad w(t) \sim NID(0, W)$$

and the discrete system. $M$, $C$ and $K$ are the $p \times p$ mass, viscous damping and stiffness matrices, respectively. $W$ is the intensity matrix of the continuous-time zero-mean Gaussian white noise $w(t)$, which by default is the identity matrix. $T$ is the sampling interval. If $T$ is larger than 0.5 times the smallest eigenperiod (the inverse of a natural eigenfrequency), a warning will be given and $T$ is altered to 90% of this eigenperiod times 0.5. By default the covariance equivalence is established for the displacements. However, by setting the boolean $disp$ to 0 it is established for the velocities instead. In this case any simulated response of the ARMAV(2,1) model will correspond to the velocities of the continuous-time system.

**Example**

Generate 1000 samples of a covariance equivalent response of a $p$-variate linear system, defined by a $p \times p$ mass matrix $M$, a $p \times p$ damping matrix $C$, and a $p \times p$ stiffness matrix $K$. Assume that the system is excited by a zero-mean Gaussian white noise excitation described by the intensity matrix $W$, and that the system is sampled using a sampling interval $T$.

The displacements are simulated as

```matlab
dds = armav21(M, C, K, T, W);
y = ddssim(dds, randn(1000, p));
```

**Reference**

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model of a continuous white noise.

Figure function of the excited system,

\[ W \]
coupled damping and of the continuous system is the identity times the smallest and will be given by setting the covariance, by setting the. In this case any nd to the velocities

\[ dds = \text{armav21}(M,C,K,T,W,0); \]
\[ ydot = \text{ddssim}(dds, \text{randn}(1000,p)); \]

See Also

ddssim, ddsstruc

Reference


armavgs

**Purpose**

ARMAV models of signals using a generalized least-squares approach.

**Synopsis**

```matlab
dds = armavgs(y, NN)
dds = armavgs(y, NN, maxiter, tol, maxsize, T, alpha, noscale)
```

**Description**

The parameters of the full polynomial ARMAV model structure

\[ A(q)y(t) = C(q)e(t) \]

are estimated using a two-stage iterative linear least-squares method, \([1,2]\).

\( y \) is a matrix with the time series data of each channel stored columnwise. \( NN \) contains initial value and structure information. The \( dds \) structure matrix is returned with the resulting parameter estimates. When no initial parameter estimates are available, enter \( NN = [na \ ns c] \), the orders of the above model. With an initial estimate available in \( ddsinit \), a DDS structure matrix of standard format enter \( NN = ddsinit \). Then the criterion minimization is initialized at \( ddsinit \).

The optional auxiliary arguments \( maxiter, tol, maxsize, T \) and \( noscale \) are explained under \( auxlsvar \).

**Algorithm**

The difference between parameter estimates is minimized iteratively using a two-stage least-squares algorithm. Each iteration starts by determine the innovations using the latest parameter estimates. On the basis of the current innovations and the previous ones an external input is determined. This external input is used in a multivariable linear least-squares ARX model to obtain new parameter estimates. The mixture of the current innovations and the previous ones in the external input are of the following form

\[ u(t) = (1 - \alpha) e_{cur}(t) + \alpha e_{prev}(t) \]

where \( u(t) \) is the external input, \( e(t) \) the innovation at time step \( t \), and \( \alpha \) is equal to \( alpha \). The reason for this mixing with the previous innovations is due to the convergence properties of the algorithm. Without this mixing the algorithm would have difficulties converging when being close to minimum. The value of \( alpha \) should always be between zero and one, and is by default 0.3.
The iterations are terminated when `maxit` is reached, or when the norm of the differences of each of the moving average parameters in two consecutive iterations, is less than `tol`.

Information about the minimization is furnished to the screen. Currently estimated parameters as well as the norm of the differences of each of the currently and previously estimated moving average parameters.

**See Also**

`armav`, `armavnn`, `auxlsvar`, `ddsstruct`

**Reference**


Purpose

Stochastic Subspace Identification of a full-polynomial ARMA$(n,n)$ model.

Synopsis

\[ \text{dds} = \text{armavnn}(y,m) \]
\[ [\text{dds},R] = \text{armavnn}(y,m,n,T,\text{algo},\text{posreal},\text{maxsize},\text{noscale}) \]
\[ [\text{dds},R] = \text{armavnn}(R) \]
\[ [\text{dds},R] = \text{armavnn}(R,n,\text{algo},\text{posreal}) \]

Description

The parameters of the full polynomial ARMA model structure

\[ A(q)y(t) = C(q)e(t) \]

are estimated using stochastic subspace method, [1].

\( y \) is a matrix with the time series data of each channel stored columnwise. The \( \text{dds} \) structure matrix is returned with the resulting parameter estimates. \( m \) is the half of the number of block rows in the Hankel matrix constructed from the data. \( n \) is the order of the auto-regressive and moving average polynomials. If not specified, the order must be determined using a plot of the singular values. After the right order there should be a significant gap between the singular values.

The recommended order is indicated by a green colour. By clicking on an order with the left mouse button the performance of this particular model can be evaluated. This evaluation is based on a comparison of the maximum singular values of the spectral densities of the data and the model. The selected model will be indicated with a red colour. To select a particular dimension click on it with the right mouse button. If the one-step ahead predictor of the selected model is unstable, this will be indicated. If this is the case, the estimated model cannot be used as initial estimate for the prediction error methods.

The string argument \( \text{algo} \) controls how the row space of the Hankel matrix containing future data is weighted and orthogonal projected onto the row space of the Hankel matrix containing past data.

If \( \text{algo} = '\text{CVAQSVD}' \) the weighting of the orthogonal projection of the row space future data onto the row space of the past data makes the algorithm correspond to the Canonical Variate Algorithm [1]. The estimation of the system matrices is based on the Quotient Singular Value Decomposition (QSVD), [2].

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v'(n,n)

model.

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cel matrix containing
space of the Hankel
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m correspond to the
ices is based on the

Algorithm

On the basis of the user supplied information the routine estimates a stochastic
state space realization using the algorithms described in [1,2]. Since the
realization is guaranteed minimal, it can be effectively converted into an
ARMAV(n,n) model using the approach described in [4].

See Also

armav, armavgls, na4sid, sspe, auxlavar, ddsstruc
Reference


Purpose

ARV models of signals using a least-squares approach.

Synopsis

```
dds = arv(y, na)
dds = arv(y, na, maxsize, T, nocovar, noscale)
```

Description

The parameters of the multivariate full-polynomial ARV model structure

\[
A(q)y(t) = e(t)
\]

are estimated using a least-squares method that solves a series of smaller subsystems in a memory and speed efficient way, [1].

Each column of the \(N \times ny\) matrix \(y\) corresponds to the time series data of one of the \(ny\) channels. \(na\) defines the model order. The dds structure matrix is returned with the resulting parameter estimates, together with estimated covariance matrices.

The optional auxiliary arguments \(maxsize, T, nocovar\) and \(noscale\) are explained under auxlsvar.

See Also

armav, armavgls, armavnn, auxlsvar, ddsstruc

Reference

Purpose

Describe auxiliary variables maxiter, tol, lim, maxsize and T.

Synopsis

help auxlsvar

Description

Most of the optimization functions have an optional argument maxsize that allows a tradeoff between memory usage and speed. Several functions allow the sampling period T to be specified. The iterative search procedures in armavgls, armav and aspem are controlled by maxiter and tol. The search procedure in armav and aspem is further controlled by lim.

maxsize: No matrix formed by the function is allowed to contain more than maxsize elements. Instead, the algorithms split the calculations into for-loops, which are slower. The default value of maxsize is set by editing iniartdi. On small machines, it is maxsize=4096. The main use of maxsize is to limit variable sizes when the algorithms run out of memory.

T: Specifying the sampling period T gives correct frequency scales on frequency domain plots, and correct time scales on domain plots. Further, the eigenfrequencies obtained from modal, and standard deviations of eigenfrequencies obtained from sdmodal will be correctly scaled. The default value is T=1.

maxiter: This variable determines the maximum number of iterations performed during search for a minimum. The default value is maxiter=10. maxiter=0 returns the results of the initial estimate.

tol: In armav and aspem the iterations are continued until the norm of the search gradient is less than tol. The iterations also terminate when the algorithm fails to find a lower value of the criterion function and when the maximum number of iterations are reached. In armavgls the iterations are continued until the norm of the differences of each of the moving average parameters in two consecutive iterations is less than tol. The iterations also terminate when the maximum number of iterations are reached. The default value is tol=0.0001.

lim: This variable determines how the criterion is modified from quadratic to one that gives linear weight to large errors. See reference for a more precise definition. Default is lim=0, which means that a non-robustified (truly quadratic) criterion is used. If the criterion needs to be robustified a good starting value is lim=1.6.

Reference

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maxsize and T. 

Current maxsize that ral functions allow the search procedures in xiter and tol. The tol. 

doled by lim. 

1 to contain more than calculations into for- 

size is set by editing 16. The main use of run out of memory. 

y scales on frequency plots. Further, the standard deviations of y scaled. The default 

number of iterations lue is maxiter=16. 

until the norm of the terminate when the function and when the 

l is the iterations are ' the moving average l. The iterations also 

ed from quadratic to ce for a more precise non-robustified (truly 

ce robustified a good 

nocovar: (Boolean)- If true (nocovar = 1) the algorithm will not estimate and store the covariance matrix of the adjustable parameters. By default (nocovar = 0), i.e. false and in this case the algorithm will estimate and store the covariance matrix. 

noscale: (Boolean)- If true (noscale = 1) the algorithm will not scale each of the output measurement channels with its sampled standard deviation. By default (noscale = 0), i.e. false and in this case the algorithm will scale the output measurements. 

Default values of these parameters are obtained either by omitting trailing arguments or by entering them as the empty matrix ( ). The default values can be altered using the routine initstdi.
Purpose
Covariance function of a linear system excited by Gaussian white noise.

Synopsis
\[ S = \text{dds2cov}(\text{dds}, n) \]

Description
The routine returns the covariance matrix \( S \) at time lags specified in the vector \( n \) of the response of a white noise excited system, described by the structure matrix \( \text{dds} \). This routine only works for stochastic systems without deterministic input [1,2].

Example
Generate a covariance equivalent ARMA V model on the basis of a continuous time linear time-invariant system, defined by a \( p \times p \) mass matrix \( M \), a \( p \times p \) viscous damping matrix \( C \), and a \( p \times p \) stiffness matrix \( K \). Assume zero mean Gaussian white noise excitation described by an intensity matrix \( W \). The system is sampled using a sampling interval \( T \). Calculate the covariance matrix at discrete time lags 0, 1, and -1 of the response of the ARMAV model

\[
\begin{align*}
\text{dds} & = \text{armav21}(M, C, K, T, U); \\
S & = \text{dds2cov}(\text{dds}, [0 1 -1]); \\
S_0 & = \text{submat}(S, 1); \\
S_1 & = \text{submat}(S, 2); \\
S_{-1} & = \text{submat}(S, 3);
\end{align*}
\]

See Also
armav21, ddsstruct

Reference

ssian white noise.

specified in the vector
scribed by the structure
ms without determinis-

e basis of a continuous
mass matrix M, a p x p
x k. Assume zero mean-
ry matrix w. The system
covariance matrix at
RMAV model

Purpose

Multipurpose routine for internal conversion of DDS structures.

Synopsis

\[
\text{ddspoly} = \text{dds2dds('SS2POLY', ddsss)} \\
\text{ddsss} = \text{dds2dds('POLY2SS', ddspoly)} \\
\text{ddas} = \text{dds2dds('CS2DS', ddas, T)}
\]

Description

\[
\text{ddspoly} = \text{dds2dds('SS2POLY', ddsss)} \text{ converts a DDS structure}
\]
\[
\text{ddsss containing a state space realization into a new structure ddspoly that}
\]
\[
\text{contains a full-polynomial model structure instead.}
\]
\[
\text{ddsss = dds2dds('POLY2SS', ddspoly) makes the opposite}
\]
\[
\text{conversion.}
\]
\[
\text{ddas = dds2dds('CS2DS', ddsc, T) converts a DDS structure ddsc}
\]
\[
\text{containing a continuous-time state space realization into a new structure ddas}
\]
\[
\text{that contains a discrete-time structure. The conversion scheme is based on the}
\]
\[
\text{zero order hold equivalence technique.}
\]

See Also

dds2poly, dds2ss, ddsstruc
Purpose
Frequency response function and noise spectral densities.

Synopsis
\[ [G, \text{NSP}] = \text{ddsfrrf}(\text{dds}, f) \]

Description
G is returned as the frequency response function estimate, and NSP (if specified) as the noise spectrum, corresponding to the dds model. If the system is free of noise, NSP is returned as the empty matrix. If dds describes a time series model, G is returned as its spectrum and NSP will returned as the empty matrix. Both discrete and continuous time models are handled.

G is stored as \( G = [G(0) \, G(1) \ldots G(N)] \) and NSP likewise. Use submat to extract individual matrices or mat2vec to extract individual channels. The routine dds2spec uses this routine to plot the frequency response function and spectral densities.

Example
Given a time series model represented by a dds model structure. Let's make a semilogarithmic plot of the auto spectral density of the first channel:

\[
\begin{align*}
N &= 512; \\
T &= \text{ddst}(\text{dds}); \\
\text{%Natural frequency 0 to Nyquist} \\
f &= 0.5 \times \left[0:N\right] / N / T; \\
G &= \text{ddsfrrf}(\text{dds}, f); \\
\text{G1} &= \text{mat2vec}(G, 1, 1); \\
\text{semilogy}(f, \text{abs}((\text{G1})))
\end{align*}
\]

If we want to investigate the DC-term this can be obtained as

\[
\text{DC} = \text{submat}(G, 1)
\]

See Also
ddsfrrf, submat, mat2vec

Reference
Structural Time Domain Identification Toolbox User's Guide
Purpose
System identification information from a model.

Synopsis
\[ [V,FPE,AIC,N,T] = dds2id(dds) \]

Description
This routine returns the FPE loss function, \( V \), Akaike's Final Prediction Error criterion, \( FPE \), and Akaike's Information Criterion, \( AIC \). These parameters can be used to evaluate the performance of the estimate. These parameters can be extracted from all identification routines even though they are not of the PEM type. Also returned are the number of samples, \( N \), and the sampling interval \( T \).

See Also
showdds, dds2t, dim, dimss, ddsstruc
dds2par

**Purpose**

Returns the parameters of a given model.

**Synopsis**

\[ \text{[par, lam, P]} = \text{dds2par(dds)} \]

**Description**

If the dds structure contains a polynomial model, \( \text{par} \) consists of the parameters of the autoregressive polynomial, the external input polynomial, and the moving average polynomial. The parameters are stored by stacking all columns of the coefficient matrices on top of each other. \( \text{lam} \) is the innovation covariance matrix, and \( \text{P} \) is the covariance matrix of the estimated parameters. \( \text{dds} \) is the model structure matrix.

If the dds structure describes a state space realization \( \text{par} \) consists of the adjustable parameters of the stacked column of the state matrices \( A, B, C, D, \) and \( K \).

**Example**

Consider a dds structure defined by a two-channel autoregressive matrix polynomial \( A \), and a two-channel moving average matrix polynomial \( C \), as

\[
A = \begin{bmatrix}
\text{eye}(2) & [1 \ 3; -5 \ 2]
\end{bmatrix}
\begin{bmatrix}
[5 \ 8; 4 \ 2]
\end{bmatrix}
\]

\[
C = \begin{bmatrix}
\text{eye}(2) & [5 \ -6; 1 \ -2]
\end{bmatrix}
\]

by creating the dds structure the parameters can be extracted,

\[
\text{dds} = \text{poly2dds}(A, [], C);
\]

\[
\text{par} = \text{dds2par}(\text{dds})
\]

\[
\begin{align*}
\text{par} & = \\
& 1 \\
& -5 \\
& 3 \\
& 2 \\
& 5 \\
& 1 \\
& -6 \\
& -2
\end{align*}
\]

**See Also**

ddsstruc, dim, dimss, dds2ss, dds2poly
Purpose
Compute or plot the prediction errors of an estimated model.

Synopsis
dds2pe(dds, z)
e = dds2pe(dds, z)

Description
dds2pe(dds, z) plots the prediction errors of the model structure dds. z is a matrix of output and input data on which the calculations are based. If the dds structure describes a time series model then z=y, where y is the output data. If the dds structure describes a model having external input then z=[y u], where u is the external input exciting the model. The routine plots all power spectral densities between zero and the Nyquist frequency of the prediction errors. It also plots all correlation functions up to time lag 20, together with the 95% confidence interval for being a realization of independent distributed stochastic variables, [1].

e = dds2pe(dds, z) returns the calculated prediction errors in e. In this case the routine will not plot the results.

See Also
ddsstruc, ddssim, dds2pred

Reference
**Purpose**

Compute the matrix polynomials associated with a given model.

**Synopsis**

\[[A, B, C, LAM] = dds2poly(dds)\]

**Description**

If the dds structure contains a polynomial model, A, B, and C are returned as the autoregressive, external input, and moving average matrix polynomials, respectively. Each of these polynomials are stored as a row of matrix coefficients. In order to extract individual matrix coefficients, use submat. If nk denotes the number of delays between external input and output, the external input matrix polynomial will have nk leading matrices containing zeros only. LAM is the innovation covariance matrix.

If the dds structure describes a state space system, the system matrices are converted according to the approach derived in [1]. In the discrete-time case all ending zero matrices are removed, i.e. matrices of the highest power in the backward shift operator. In the continuous-time case all leading zero matrices are removed, i.e. the matrices in the highest power of the differential operator. LAM is the innovation covariance matrix.

**See Also**

ddsstruc, dim, dds2ss, dds2par

**Reference**

Purpose

Compute or plot the one-step ahead prediction of an estimated model.

Synopsis

dds2pred(dds, z)

yhat = dds2pred(dds, z)

Description

dds2pred(dds, z) plots the measured response given in z and predicted response of the model structure dds [1,2]. The FFT-based spectral densities of both measured and predicted response are also plotted. z is a matrix of output and input data on which the calculations are based. If the dds structure describes a time series model then z = y, where y is the output data. If the dds structure describes a model having external input then z = [y' u'], where u is the external input exciting the model. The routine plots the measured and predicted response. Also, it plots all power spectral densities between zero and the Nyquist frequency of both measured and predicted response. In all cases the measured response is plotted behind the predicted.

yhat = dds2pred(dds, z) returns the predicted response in yhat. In this case the routine will not plot the results.

See Also

ddsstruct, ddssim, dds2 pes

Reference


dds2spec

Purpose
Plot frequency response function and noise spectral densities.

Synopsis
dds2spec(option, dds)
dds2spec(option, dds, f)

Description
If option = 'PSD' all absolute values of the frequency response functions of the system contained in the dds structure matrix are plotted. If the system also includes a noise term its auto and cross spectral densities are also plotted. If dds describes a time series model all absolute values of the auto and cross spectral densities of the response of this model are plotted, [1].

If option = 'SVD' all singular values of the frequency response functions of the system contained in the dds structure matrix are plotted. If the system also includes a noise term, the singular values of its spectral densities are also plotted. If dds describes a time series model, the singular values of the spectral densities of the response of this model are plotted, [1].

The input argument f should be a vector of frequencies to be plotted. This is especially applicable for the continuos-time models. By default 256 frequency points between 0 and the Nyquist frequency are plotted. The Nyquist frequency is determined on the basis of the absolute value of sampling interval contained in the dds structure.

See Also
ddsstruc, dds2frf

Reference
Purpose

Convert the DDS structure to an innovation state space realization.

Synopsis

\[ \{ A, B, C, D, K, X0, \lambda \} = \text{dds2ss}(\text{dds}) \]
\[ \{ A, B, C, D, K, X0, \lambda \} = \text{dds2ss}(\text{dds}, \text{doabal}) \]

Description

Converts the dds model structure matrix into the following innovation state space system:

\[
x(t_{i+1}) = Ax(t_i) + Bu(t_i) + Ke(t_i)
\]
\[
y(t_i) = Cx(t_i) + Du(t_i) + e(t_i)
\]

where \( A \) is the state space matrix, \( B \) is the external input matrix, \( K \) is the Kalman gain matrix, \( C \) is the observation matrix, and \( D \) is the auxiliary observation matrix. \( X0 \) is default initial values of the state vector, and \( \lambda \) is the innovation covariance matrix. By default the returned realization is of the Observability canonical form, \([2]\). However, by setting the boolean \text{doabal} to \text{I} (true), the returned realization will be balanced according to \([3]\). By default \text{doabal} is \text{0} (false).

Example

Given a time series model represented by a dds model structure, and given some measurements \( y \); it is very easy to convert to innovation state space form, in order to obtain the predicted response \( \hat{y} \) and the prediction errors \( e \):

\[
[ A, B, C, D, K, X0 ] = \text{dds2ss}(\text{dds});
\]
\[
% B and D will be empty because
% dds describes a time series model
Xhat = ltitr([A-K*C,K,y,X0]);
yhat = (C'*Xhat)';
e = y-yhat;

See Also

\text{ddsstruc}, \text{dds2par}, \text{dds2pred}, \text{dds2pe}
Reference


dds2t

**Purpose**
Return the sampling interval on which a model is based.

**Synopsis**
\[ T = dds2t(dds) \]

**Description**
\( T \) is the sampling interval of the model \( dds \).

**See Also**
ddsstruc, t2dds
ddssim

Purpose
Simulate the response of a model.

Synopsis
\[ y = \text{ddssim}(dds, z) \]
\[ [y, e] = \text{ddssim}(dds, z) \]

Description
Simulate the response \( y \) of an input-output model

\[
A(q)y(t) = B(q)u(t) + C(q)e(t), \quad \epsilon(t) \sim \text{NID}(0, \Sigma)
\]

or an innovation state space realization

\[
x(t) = Ax(t) + Bu(t) + Ke(t), \quad \epsilon(t) \sim \text{NID}(0, \Lambda)
\]

\[
y(t) = Cx(t) + Du(t) + e(t)
\]

described by the \( dds \) structure matrix. If \( dds \) describes a time series model, i.e. \( B \) is not present in any of the above model descriptions, \( z \) is equal to a sequence of independent Gaussian distributed random numbers, i.e. \( z = e \). If the model also contains the external input term, \( z \) also contains the external (or deterministic) input \( u \), i.e. \( z = [u, e] \).

The random numbers in \( a \) are correlated and scaled in order to have a covariance matrix equal to \( \Sigma \). The innovation sequence obtained from this operation is on output given in \( e \).

Example
Given a time series model represented by a \( dds \) model structure, let's simulate a sequence of 1000 samples. Assume that the model has four outputs. In this case the simulated response \( ysim \) and the innovations \( e \) can be obtained as

\[
z = \text{randn}(1000,4);
\]

\[
[ysim, e] = \text{ddssim}(dds, z);
\]

See Also
\texttt{ddsstruc, dds2pred}

Reference
Structural Time Domain Identification Toolbox User's Guide
If: \( N \in N(D(O, A)) \)

\[ \mathbf{z} = \phi(\mathbf{e}) \]

\( t \) is equal to a sequence of external (or deterministic) time series model, i.e. \( z = \mathbf{e} \). If the model has a covariance on this operation is on

\[ x(t_{n+1}) = Ax(t_n) + Bu(t_n) + Ke(t_n) \]

\[ y(t_n) = Cx(t_n) + Du(t_n) + e(t_n) \]


**Purpose**

Description of the DDS structure matrix.

**Synopsis**

`help ddsstruc`

**Description**

The DDS (Data Dependent System) structure matrix stores information about a given model, derived from the polynomial model

\[ A(q)y(t) = B(q)u(t) + C(q)e(t) \]

or the innovation state space model structure

\[ x(t_{n+1}) = Ax(t_n) + Bu(t_n) + Ke(t_n) \]

\[ y(t_n) = Cx(t_n) + Du(t_n) + e(t_n) \]

It stores the following general information:

- Number of output channels.
- Innovation covariance matrix.
- Loss function.
- Akaike's Final Prediction Error (FPE).
- Sampling interval.
- Number of measurements used for the estimation.
- An identifier for the routine that generated it.
- The time it was generated.
- Model parameters.
- Estimated covariance matrix of the model parameters.
In the case of the polynomial model the DDS structure is organized in the following way.

**Row 1, Column 1 to 17:**
- na: Auto regressive polynomial order
- nb: External input polynomial order
- nc: Moving average polynomial order
- nk: Number of delays between external input and output
- ny: Number of output channels
- T: Sampling period (Default $T=1$)
- type: Type identifier of identification routine
- fpe: Akaike's FPE criterion
- N: Number of measurements
- date: (year, month, day) of creation
- time: (hour, minute) of creation
- V: Loss function that corresponds to the estimated parameters
- nu: Number of input channels
- nocovar: Boolean. 1 - No covariance matrix of the parameters is stored. 0 - Estimated covariance matrix of the parameters is stored.

**Row 2, Column 1 to ny^2:**
- lam: Innovation covariance matrix (Default the zero matrix)

**Row 2, Column ny^2+1 to 2ny^2:**
- scl: Output scaling matrix (Default the identity matrix)

**Row 3, Column 1 to $(na+nc)*ny^2+nb*nu*ny$:**
- par: Parameters of the estimated autoregressive and moving average polynomials.

**Row 4 to $3+(na+nc)*ny^2+nb*nu*ny$: Column 1 to $(na+nc)*ny^2+nb*nu*ny$: (if nocovar=0):**
- P: Covariance matrix of estimated parameters (Default zero matrix)
In the case of the state space description the DDS structure is organized in the following way.

Row 1, Column 1 to 16:
- na: State space dimension, i.e. $\dim(A)$
- nb: Number of columns of the external input matrix $B$
- nc: Number of rows of the observation matrix $C$
- nk: Number of columns of the Kalman gain matrix $K$
- ny: Number of output channels ($ny=nc$)
- T: Sampling period (Default $T=1$)
- type: Type identifier of identification routine
- fpe: Akaike's FPE criterion
- N: Number of measurements
- date: (year, month, day) of creation
- time: (hour, minute) of creation
- V: Loss function that corresponds to the estimated parameters
- nocovar: Boolean. 1 - No covariance matrix of the parameters is stored. 0 - Estimated covariance matrix of the parameters is stored.

Row 2, Column 1 to $ny^2$:
- y: Observation matrix (Default the identity matrix)
- x: Initial state vector (Default a vector of zeroes)

Row 2, Column $ny^2 + 1$ to $2ny^2$
- scl: Output scaling matrix (Default the identity matrix)

Row 2, Column $2ny^2$ to $3ny^2$
- $x_0$: Initial state vector (Default a vector of zeroes)

Row 3 Column 1 to $(na^2 + na nb + nc na + nc nb + ncnk)$:
- par: Parameters of the state space system, stored as $par = [A(:) B(:) C(:) D(:) K(:)]$

Row 4 Column 1:
- Nest: Number of estimated parameters in the model

Row 4 Column 2 to Nest+1:
- Indx: Index of estimated parameters of par

Row 5 Column 1 to Nest: (if nocovar=0)
- P: Covariance of estimated parameters
Purpose

Extract the dimensions of the matrix polynomials describing the DDS structure.

Synopsis

\[ n = \text{dim}(\text{dds}) \]
\[ [na, nb, nc, nk, ry, nu] = \text{dim}(\text{dds}) \]

Description

The dimensions of the polynomial model form of the DDS structure

\[ A(q)y(t_k) = B(q)u(t_k-nk) + C(q)e(t_k) \]

are extracted.

\( na, nb \) and \( nc \) is the autoregressive, external input, and moving average order, respectively. \( ry \) is the number of output channels, and \( nu \) is the number of input channels. \( nk \) is the number of delays between the external input and the system response. If only one output arguments is specified then \( n \) is returned as \( na \) times \( ry \) (the state space dimension).

See Also

ddsstruc, dimss, dds2meas
Purpose

Extract the dimensions of the state space system that describes the DDS structure.

Synopsis

\[ [na, nb, nc, nk] = \text{dimss}(dds) \]

Description

The dimensions of the innovation state space system

\[
\begin{align*}
\dot{x}(t_k) &= Ax(t_k) + Bu(t_k) + Ke(t_k) \\
y(t_k) &= Cx(t_k) + Du(t_k) + e(t_k)
\end{align*}
\]

are extracted.

\( na \) is the dimension of the square state matrix \( A \). \( nb \) is the number of columns of the external input matrix \( B \). \( nc \) is the number of rows (or output) of the observation matrix \( C \), and \( nk \) is the number of columns of the Kalman gain matrix \( K \).

The dimensions of each of the matrices describing the system are the:

\[
\begin{align*}
\text{dim}(A) &= na \times na \\
\text{dim}(B) &= na \times nb \\
\text{dim}(C) &= nc \times na \\
\text{dim}(D) &= nc \times nb \\
\text{dim}(K) &= na \times nk
\end{align*}
\]

See Also

\texttt{ddsstruc}, \texttt{dim}, \texttt{dds2meas}
Purpose

Correlation and covariance function estimate for a data matrix.

Synopsis

\[
\begin{align*}
C &= \text{fftcor}(y, n) \\
G &= \text{fftcov}(y, n)
\end{align*}
\]

Description

\[
\begin{align*}
C &= \text{fftcor}(y, n) \text{ estimates the one-sided correlation functions from lag 0 to lag } n-1. \text{ On output, } C \text{ is the correlation matrices for each lag are stored in row starting with lag } 0. \\
G &= \text{fftcov}(y, n) \text{ estimates the one-sided covariance functions from lag 0 to lag } n-1. \text{ On output, } G \text{ is the covariance matrices for each lag are stored in row starting with lag } 0.
\end{align*}
\]

In both cases \( y \) is a matrix storing the data to be processed. The channels are stored column-wise. \( n \) is the number of returned submatrices in \( C \) and \( G \). Use \text{submat} to extract individual correlation or covariance matrices, and use \text{mat2vec} to extract a specific element from each matrix.

Algorithm

The routines calculates an unbiased estimate of the auto and cross correlation functions using FFT combined with a Bartlett triangular lag window. An unbiased estimate is achieved by extending each data segment by padding zeroes at the ends up to the double size. This procedure ensures that the estimate is only biased by the window. Because of this the bias can be removed by multiplication by the inverse window.

The covariance function is obtained on the basis of the correlation function which is scaled using a zero lag covariance estimate obtained by using the routine \text{cov}.

See Also

\text{fftspec}, \text{cov}, \text{submat}, \text{mat2vec}
The channels are C and G. Use matrices, and use cross correlation lag window. An nent by padding is that the estimate n be removed by relation function ned by using the

**fftspec**

**Purpose**

Power spectrum estimation of a data matrix.

**Synopsis**

\[ P = \text{fftspec}(y) \]

\[ [P,f] = \text{fftspec}(y,nfft,noverlap,T) \]

**Description**

Estimate the Power Spectral Density of signals stored columnwise in \( y \) using Welch's averaged periodogram method. The signals of \( y \) are divided into overlapping sections, each of which is detrended and windowed, then zero padded to length \( nfft \). The overlap is specified by \( noverlap \).

\( P \) is returned as the multivariate spectral densities. Each frequency is described by a square spectral density matrix. These matrices are stored in a row starting with the DC term. Use \( \text{submat} \) to extract individual spectral density matrices and \( \text{mat2vec} \) to extract a specific element from each spectral density matrix.

Given a sampling period \( T \) the vector \( f \) is returned as the frequencies at which the PSD is estimated. If \( T \) is not specified the frequencies lie between 0 and 1.

The default values for the parameters are \( nfft = 256 \) (or size(\( y \)) whichever is smaller), \( noverlap = 0 \), \( T = 0.5 \) (i.e. Nyquist frequency is 1).

If no output arguments are specified, the routine plots the auto spectral densities and the absolute values of the cross-spectral densities.

**See Also**

\( \text{fftcov} \), \( \text{fftcov} \), \( \text{submat} \), \( \text{mat2vec} \)
**initpem**

**Purpose**
Generate initial information for `sspem`.

**Synopsis**
```
ddsinit = initpem(dds)
ddsinit = initpem(dds, operation, elements)
```

**Description**
The structure matrix `dds` of the standard format contains the initial information to use. The DDS structure is on output returned in `ddsinit` together with the information about which parameters are adjustable. `operation` is a string that controls how the routine creates `ddsinit`. This string has the following options:

- `operation = 'MATRIX'`: A manual option for selecting adjustable parameters with `MATRIX` indicating which of the system matrices to manipulate (one of 'A', 'B', 'C', 'D' or 'K'). When using this option `elements` is an n x 2 matrix that contains the row and column numbers of the elements to be marked adjustable. If the argument `elements` is omitted all the elements of the system matrix are marked adjustable.

- `operation = 'auto'`: Using this option the routine will return `ddsinit` as a transformed observability canonical state space realization and automatically generate the index of adjustable parameters in the model. NOTE that this option is the default one and that it must be used if the DDS structure contains a polynomial model.

- `operation = 'unlock'`: This option unlocks all parameters. In other words, it makes all parameters adjustable.

- `operation = 'lock'`: This option locks all parameters. In other words, it makes all parameters non-adjustable.

It should be noted that any covariance matrix of prior adjustable parameters in the DDS structure is deleted using all options except `operation = 'unlock'`.

**See Also**
`sspem`, `ddsstruct`

---

References

"Structural Time Domain Identification Toolbox User's Guide"
**Purpose**

Configuration and initialization of default parameters.

**Synopsis**

`initstdi`

**Description**

`initstdi` edits the default parameters stored in the `stdi.mat` configuration file. Should this file get lost the routine can also be used to reconstruct it.

The routine is menu driven. Currently values as well as default values of the editable parameters are presented. The following options are available

1. Retrieve Default Configuration
2. Edit Plot and Axis Font Sizes
3. Edit PEM Optimization Parameters
4. Edit Sampling Interval
5. Help
6. Save and Quit
7. Quit

The default configuration (1) sets all parameters and font sizes to default values. The font sizes can be edited by the option (2). The algorithms implementing the prediction error method for different model structures also need to be configured which is performed by the option (3). If a particular sampling interval is used frequently this can be set by the option (4). Help is provided by the option (5) and the configuration is saved using option (6). After saving the routine quits. This can also be accomplished without saving using option (7).

**See Also**

`auxisvar`
isdds

**Purpose**
Check if a matrix is a DDS structure.

**Synopsis**
\[ B = \text{isdds}( A ) \]

**Description**
B is a boolean. If A is a DDS structure then B=1, otherwise B=0.
isddscs

Purpose
Check if a DDS structure contains a continuous-time system.

Synopsis
\[
B = \text{isddscs}(dds)
\]

Description
B is a boolean. If dds contains a continuous-time state space description then B=1, otherwise B=0.
isddss

**Purpose**
Check if a DDS structure contains a state space realization

**Synopsis**

\[ B = \text{isddss}(dds) \]

**Description**

\( B \) is a boolean. If \( dds \) contains a state space description then \( B=1 \), otherwise \( B=0 \).
mat2vec

**Purpose**

Extract a specific element from all submatrices stored in a row.

**Synopsis**

\[ y = \text{mat2vec}(x,r,c) \]
\[ y = \text{mat2vec}(x,r,c,n) \]

**Description**

\( x \) is a row vector of square matrices. This routine extracts the \( r,c \) element of each of the submatrices, where \( r \) is the row index and \( c \) the column index. All extracted elements are stored in the row vector \( y \). If the submatrices are not square, the number of columns of each submatrix is specified in \( n \).

**Example**

Consider the following row matrix \( A \) consisting of three square submatrices

\[
A = \begin{bmatrix}
1 & 2 & 5 & 8 & 0 & 7 \\
5 & 6 & 10 & 5 & 1 & 6
\end{bmatrix}
\]

Extract element 1,2 of each submatrix and store all extracted elements in \( B \)

\[
B = \text{mat2vec}(A,1,2)
\]

\[
B = \begin{bmatrix}
2 & 8 & 7
\end{bmatrix}
\]

**See Also**

submat, dds2spec
mck2dds

Purpose
Convert from a continuous-time second order differential system into a DDS structure.

Synopsis
dds = mck2dds(M, C, K)
dds = mck2dds(M, C, K, S, OUTPUT)

Description
Convert the second order linear time-invariant continuous-time system described the differential equation

\[ M\ddot{y}(t) + C\dot{y}(t) + Ky(t) = Su(t) \]

where \( M, C \) and \( K \) are the mass, damping and stiffness matrices, respectively, into a continuous-time state space realization stored in the dds structure matrix. \( S \) is a selection or resolution matrix, which by default is set to the identity matrix.

The OUTPUT argument is a character that controls what type of output the state space system gives. If OUTPUT='d' the output is displacements, if OUTPUT='v' the output is velocities, and if OUTPUT='a' the output is accelerations.

See Also
armav21, ss2dds
Purpose

Modal decomposition and modal parameter extraction of a model.

Synopsis

\[ \{\psi, \mu\} = \text{modal}(\text{dds}, 'MDCMP') \]

\[ \{\phi, \text{freq}, \zeta\} = \text{modal}(\text{dds}) \]

\[ \{\phi, \text{freq}, \zeta\} = \text{modal}(\text{dds}, \text{norm}) \]

Description

Depending on the input arguments, this routine returns either a modal decomposition or modal parameters of a model stored in a DDS structure.

\[ \{\psi, \mu\} = \text{modal}(\text{dds}, 'MDCMP') \] performs a modal decomposition of the model stored in dds. On output \(\psi\) is the complex modal matrix. The columns of this matrix are the eigenvectors of the state space matrix. The corresponding eigenvalues are returned in \(\mu\). [1,2].

\[ \{\phi, \text{freq}, \zeta\} = \text{modal}(\text{dds}) \] returns the modal parameters of the model stored in dds. The scaled mode shapes are returned as the columns of the matrix \(\phi\). By default, the normalization of the mode shapes is determined by the routine \text{eig}. However, by supplying an extra boolean argument \text{norm} the normalization can be performed with respect to the bottom row of \(\phi\). In this case \text{norm} is set \(1\) (true). By default \text{norm} is \(0\) (false).

\text{freq} is a vector of the corresponding natural eigenfrequencies scaled with respect to the sampling interval of the model. \text{zeta} is a vector of corresponding damping ratios.

All modal parameters are sorted so that the natural eigenfrequencies are stored in ascending order.

See Also

ddsstruc, sdmodal

Reference


Structural Time Domain Identification Toolbox User's Guide 4-43
Purpose

Check the consistency of a matrix polynomial.

Synopsis

msg = mpcheck(pol)
msg = mpcheck(pol, ismonic, ncolsub)

Description

pol is a matrix polynomial stored as a row of square matrices. msg = mpcheck(pol) checks the consistency of pol. pol must not have fewer columns than rows. The number of columns divided with the number of rows must equal an integer. By default the routine assumes and check that the matrix polynomial is monic, i.e., has a leading identity matrix. The checking of this can be disabled by setting the boolean ismonic to zero. The routine also by default assumes that the number of columns in each matrix coefficient is equal to its number of rows. This can be changed by specification of ncolsub.

See Also

mpfilt, mpconv, mpdeconv

Reference

Structural Time Domain Identification Toolbox User’s Guide
Purpose
Multivariate convolution and deconvolution, or matrix polynomial multiplication and division.

Synopsis
c = mpconv(a,b)
[q,r] = mpdeconv(b,a)

Description
a and b are row vectors of square matrices. mpconv(a,b) convolves a and b. The matrix convolution sum is

\[ c(n+1) = \sum_{k=0}^{N-1} a(k+1)b(n-k) \]

where N is the maximum sequence length. [q,r] = mpdeconv(b,a) deconvolves a out of b, using long division. The result (quotient) is returned in matrix q and the remainder in matrix r so that \[ b = \text{conv}(q,a) + r \]. If a and b are row vectors of matrix polynomial coefficients, then to convolve them is equivalent to multiplying the two polynomials, and deconvolution is polynomial division. The result of dividing b by a is quotient q and remainder r.

Example
Consider two monic 2-channel matrix polynomials a and b, defined as

\[ a = [\text{eye}(2); [1 3; -5 2]; [5 8; 4 2 ]]; \]
\[ b = [\text{eye}(2); [5 -6; 1 -2 ]]; \]

the convolution (or polynomial multiplication) is

\[ c = \text{mpconv}(a,b) \]

\[ c = \begin{bmatrix} 1 & 0 & 6 & -3 & 40 & 11 & 1 & 28 \\
0 & 1 & -4 & 0 & 15 & 1 & -3 & 4 \end{bmatrix} \]

Use deconvolution to divide a back out again

\[ [q,r] = \text{mpdeconv}(c,a) \]

\[ q = \begin{bmatrix} 1 & 0 & 5 & -6 \\
0 & 1 & 1 & -2 \end{bmatrix} \]
Purpose
Filtering of multivariate linear systems.

Synopsis
\[ y = \text{mpfilt}(b,a,x) \]
\[ (y, zf) = \text{mpfilt}(b,a,x,zi) \]

Description
\texttt{mpfilt} filters data using a multivariate digital filter based on state space filtering. The filter handles both multivariate FIR and multivariate IIR filters. Access to initial and final conditions is available.

\[ y = \text{mpfilt}(b,a,x) \] filters the data in the matrix \( x \) with the filter described by the vectors of matrix polynomial coefficients given in matrices \( a \) and \( b \) to create the matrix \( y \). Each column of \( x \) and \( y \) corresponds to a channel of data. The operations performed by \texttt{mpfilt} are described in time domain by the difference equation

\[ y(n,:) = \text{submat}(b,1)*x(n,:) + \text{submat}(b,2)*x(n-1,:) + \ldots + \text{submat}(b,nb+1)*x(n-nb,:) - \text{submat}(a,2)*y(n-1,:) - \ldots - \text{submat}(a,na+1)*y(n-na,:) \]

If the first coefficient matrix of \( a \) is different from the identity matrix, all filter coefficients will be normalized by pre-multiplying the coefficient matrices with the inverse of the first coefficient matrix. When use is made with two left-hand arguments, \texttt{mpfilt} returns the final conditions on the states

\[ (y, zf) = \text{mpfilt}(b,a,x) \]

When use is made with an extra right-hand argument, initial conditions on the states are specified

\[ y = \text{mpfilt}(b,a,x,zi) \]

The size of the initial/final conditions must be \( 2 \times \text{max}(na,nb) \times p \), where \( p \) is the number of channels.

Example
Consider two monic 2-channel matrix polynomials \( a \) and \( b \), defined as
\[ a = [\text{eye}(2) \ [1 \ 3; -5 \ 2] \ [5 \ 8; 4 \ 2]], b = [\text{eye}(2) \ [5 \ -6; 1 \ -2]] \]
and an input matrix
\[ x = [1 \ 1; 0 \ 0; 0 \ 0] \]
Filter \( x \) using \( b \) and \( a \) as

\[ y = \text{mpfilt}(b, a, x) \]

to yield

\[ y = \begin{bmatrix} 1 & 1 \\ -5 & 2 \\ -14 & -35 \end{bmatrix} \]

See Also

filter, ltitr, mpcheck, mpconv, mpdeconv
Purpose

Return the order and the number of channels of a matrix polynomial.

Synopsis

\[ \begin{align*}
    [n,p] & = \text{mporder}(a) \\
    [n,p] & = \text{mporder}(a, \text{ncolsub})
\end{align*} \]

Description

\( a \) is a matrix polynomial stored in a row of matrix polynomial coefficients. \( [n,p] = \text{mporder}(a) \) returns the order of the polynomial in \( n \) and the number of channels in \( p \). By default, the routine assumes that the number of columns in each matrix coefficient is equal to its number of rows. This can be changed by specification of \( \text{ncolsub} \).

Example

Consider a monic 2-channel matrix polynomial \( a \) defined as

\[
    a = \begin{bmatrix}
        \text{eye}(2) & [1, 3; -5, 2] & [5, 8; 4, 2]
    \end{bmatrix}
\]

\[
    a =
    \begin{bmatrix}
        1 & 0 & 1 & 3 & 5 & 8 \\
        0 & 1 & -5 & 2 & 4 & 2
    \end{bmatrix}
\]

Determine the polynomial order

\( [n,p] = \text{mporder}(a) \)

to yield

\[
    n = 2
\]

\[
    p = 2
\]
Purpose
Stochastic Subspace Identification of an innovation state space realization.

Synopsis
\[
dds = \text{na4sid}(y, m)
\]
\[
[dds, R] = \text{na4sid}(y, m, n, T, \text{algo}, \text{posreal}, \text{maxsize}, \text{noscale})
\]
\[
[dds, R] = \text{na4sid}(R)
\]
\[
[dds, R] = \text{na4sid}(R, n, \text{algo}, \text{posreal})
\]

Description
The parameters of the stochastic innovation state space system
\[
x(t_{i+1}) = Ax(t_i) + K e(t_i), \quad e(t_i) \sim NID(0, \Lambda)
\]
\[
y(t_i) = C x(t_i) + e(t_i)
\]
are estimated using stochastic subspace state space identification, [1].

\(y\) is a matrix with the time series data of each channel stored columnwise. \(n\) is the desired state space dimension, and \(m\) is equal to the half number of block rows in the Hankel matrix constructed from the data. \(n\) is the state space dimension. If not specified, it must be determined using a plot of the singular values. After the right state space dimension there should be a significant gap between the singular values.

The recommended state space dimension is indicated by a green colour. By clicking on a dimension with the left mouse button the performance of this particular realization can be evaluated. This evaluation is based on a comparison of the maximum singular values of the spectral densities of the data and the realization. The selected state space dimension will be indicated with a red colour. To select a particular dimension click on it with the right mouse button. If the one-step ahead predictor of the selected realization is unstable, this will be indicated. If this is the case, the estimated realization cannot be used as initial estimate for the Prediction Error Methods.

The string argument \(\text{algo}\) controls how the row space of the Hankel matrix containing future data is weighted and orthogonal projected onto the row space of the Hankel matrix containing past data.

If \(\text{algo} = 'CVAQSVD'\) the weighting of the orthogonal projection of the row space future data onto the row space of the past data makes the algorithm correspond to the Canonical Variate Algorithm, [1]. The estimation of the system matrices is based on the Quotient Singular Value Decomposition (QSVD), [2].

Reference

Structural Time Domain Identification Toolbox User’s Guide
If $\text{algo} = \text{CVA}$ the weighting of the orthogonal projection of the row space future data onto the row space of the past data makes the algorithm correspond to the Canonical Variate Algorithm. The estimation of the system matrices is based on a combined QR and Singular Value Decomposition (SVD) approach, [1]. By default $\text{algo} = \text{CVA}$.

If $\text{algo} = \text{PC}$ the weighting of the orthogonal projection of the row space future data onto the row space of the past data makes the algorithm correspond to the Principal Component algorithm, [1,3]. The estimation of the system matrices is based on a combined QR and Singular Value Decomposition (SVD) approach.

If $\text{algo} = \text{UPC}$ the weighting of the orthogonal projection of the row space future data onto the row space of the past data makes the algorithm correspond to the Unweighted Principal Component algorithm, [1]. The estimation of the system matrices is based on a combined QR and Singular Value Decomposition (SVD) approach.

If the boolean argument $\text{posreal}$ is true ($\text{posreal}=1$) a positive real solution of the steady-state covariance matrix is enforced. This is a necessary requirement for a correct estimation of the moving average and the innovation covariance matrix. If $\text{posreal}$ is false ($\text{posreal}=0$), which it is by default, a positive real solution is not guaranteed and it might result in, e.g. bad spectral density plots or simulations. A warning will be given if the solution is not positive real.

If different state space dimensions $n$ will be tried for the same $y$ and $m$ the matrix $R$ contains the necessary information needed for subsequent calls. For these subsequent calls the routine should be called in one of the following ways:

\[
[\text{dds}, R] = \text{na4sid}(R)
\]

\[
[\text{dds}, R] = \text{na4sid}(R, n, \text{algo}, \text{posreal})
\]

Again if $n$ is not specified, it must be determined from the singular values plot. Finally, please note that $m$ and $n$ must satisfy the inequality: $m \geq np$, where $p$ is the number of columns of $y$. In practice for noisy data $m$ should be much larger than $np$.

The optional auxiliary arguments $\text{maxsize}, \text{T}$ and $\text{noscale}$ are explained under auxlsvar.

**Algorithm**

On the basis of the user supplied information the routine estimates a stochastic state space realization using the algorithms described in [1,2].

**See Also**

armavnn, aspem, ssmbh, armav, armavpls, auxlsvar, ddsstruc
Reference


par2dds

**Purpose**
Create a DDS structure from parameters of a polynomial model.

**Synopsis**

```matlab
dds = par2dds(par, na, nb, nc, nk, ny)
dds = par2dds(par, na, nb, nc, nk, ny, nu, lam, P)
```

**Description**
If the model is of a polynomial form

\[ A(q)y(t) = B(q)u(t) + C(q)e(t) \]

then `par` is a vector of stacked columns of the polynomial coefficients of the autoregressive polynomial \( A(q) \), the external input polynomial \( B(q) \), and the moving average polynomial \( C(q) \). `na` is the autoregressive polynomial order, `nb` is the external input polynomial order, and `nc` is the moving average polynomial order. `nk` is the number of delays between external input and output. `ny` is the number of outputs, and `nu` is the number of inputs. `lam` is the innovation covariance matrix and `P` is the covariance matrix that corresponds to `par`. If the model is a state space realization, use `ss2dds` instead.

**See Also**

`ddsstruc`, `dds2par`, `ss2dds`
poly2dds

**Purpose**
Create a DDS structure from matrix polynomials.

**Synopsis**

```matlab
dds = poly2dds(A)
dds = poly2dds(A,B,C,nu,nk, lam,P)
```

**Description**

A is an autoregressive matrix polynomial, B is an external input matrix polynomial, and C is a moving average matrix polynomial. `nu` is number of input channels. This should only be specified if the number of input is different from the number of output. `nk` is the number of delays between the external input and the output. `lam` is the innovation covariance matrix. `P` is the covariance matrix of the estimated parameters stored in the format that corresponds to the parameter vector returned from `dds2par`. The routine returns as `dds` the DDS structure matrix.

**See Also**

`ddsstruc`, `dds2par`, `dds2poly`

---

Reference

Structural Time Domain Identification Toolbox User's Guide
Purpose

Estimated uncertainties of modal parameters.

Synopsis

\[
\begin{align*}
\text{[sdphi, sdfreq, sdzeta]} & = \text{sdmodal(dds)} \\
\text{[sdphi, sdfreq, sdzeta, Pphi, Pfreq, Pzeta]} & = \text{sdmodal(dds)}
\end{align*}
\]

Description

The standard deviations and covariance matrices of the modal parameters of a discrete-time model are estimated using numerical differentiation.

The standard deviations of the scaled mode shapes are returned as the matrix \(sdphi\) and organized just as the mode shapes returned by modal. In other words, each column contains the standard deviations of a scaled mode shape. For numerical stability the standard deviations are returned for mode shapes that are normalized with respect to their bottom element.

\(sdfreq\) is a vector of standard deviations of the corresponding natural eigenfrequencies. \(sdzeta\) is a vector of standard deviations of the corresponding damping ratios.

Supplied with the extra output arguments, \(sdmodal\) returns \(Pphi\) as the full covariance matrix of the scaled mode shapes, \(Pfreq\) as the full covariance matrix of the natural eigenfrequencies, and \(Pzeta\) as the full covariance matrix of the damping ratios.

Algorithm

The covariance matrices of the modal parameters are obtained by a linear transformation of the covariance matrix of the estimated parameters, \([1]\). This linear transformation corresponds to a Taylor expansion of the mean values of the modal parameters. This transformation involves the construction of a transformation matrix. Having obtained the covariance matrices of the modal parameters, the standard deviations are calculated as the square roots of the diagonal elements.

See Also

\(ddsstruc, \text{modal}\)

Reference


Structural Time Domain Identification Toolbox User's Guide
**Purpose**
Display the information in the DDS structure matrix on the screen.

**Synopsis**
showdds (dds)

**Description**
If dds contains a input-output model, this routine displays the nonempty matrix polynomials of the model dds, together with their standard deviations given as fake imaginary parts.

If instead the dds structure contains a state space description, the nonempty state space matrices are displayed.

Also displayed are:
- Type of model
- Number of channels
- Name of routine that created the structure
- Creation time
- Number of samples used for the creation
- Sampling interval
- Loss function
- Akaike's Final Prediction Error Criterion (FPE)
- Innovation covariance matrix.
- Scaling matrix of the output measurements.

**See Also**
ddastruc

*Reference*
Structural Time Domain Identification Toolbox User's Guide
speccmp

Purpose

Compare spectral densities of one or several DDS structures with response data.

Synopsis

```
speccmp(dds, y)
speccmp(project, n)
speccmp(project, n, y)
```

Description

`speccmp(dds, y)` compares the absolute values of the auto and cross spectral densities of the DDS structure matrix `dds`, and response data `y`, where each column of `y` is a measurement channel. The auto and cross spectral densities of `y` are calculated using FFT.

`speccmp(project, n)` compares several DDS structures with each other. The DDS structures to be compared are saved under the variable name `dds` in `*.MAT` files. The names of the files are concatenations of the string `project` and an integer starting from 1 and going to `n`, as:

```
for i=1:n
    file = [project,int2str(i)]
end
```

`speccmp(project, n, y)` compares the DDS structures with response data in `y`.

This routine only works for discrete time series models.

See Also

ddsstruc, dds2spec, spectrum
Purpose
Create a DDS structure of an innovation state space realization.

Synopsis

\[
\text{dds} = \text{ss2dds}(A, B, C)
\]

\[
\text{dds} = \text{ss2dds}(A, B, C, D, K, X0, T, \lambda, P, \text{indx})
\]

Description
Convert from an innovation state space system of the type

\[
\begin{align*}
\dot{x}(t) &= Ax(t) + Bu(t) + Ke(t), \quad e(t) \sim NID(0, \Lambda) \\
y(t) &= Cx(t) + Du(t) + e(t)
\end{align*}
\]

where \( A \) is the state space matrix, \( B \) is the external input matrix, \( K \) is the Kalman gain matrix, \( C \) is the observation matrix, and \( D \) is the direct term matrix, into a DDS structure matrix. Initial conditions of the state vector \( x(t_0) \) are supplied in \( X0 \). The innovation covariance matrix \( \Lambda \) is supplied in \( \lambda \), [1].

Assume that the parameters of the realization are assembled in one vector \( \theta \) by stacking all columns of \( A, B, C, D \) and \( K \) on top of each other. If a covariance matrix of the adjustable parameters exists then it can be supplied in \( P \). In this case \( \text{indx} \) is entered as a vector of coordinates of the locations of the adjustable parameters in \( \theta \).

See Also

\text{ddsstruc}, \text{poly2dds}, \text{ds2ss}

Reference

sscheck

**Purpose**
Check the dimensional consistency of a state space system.

**Synopsis**
\[ \text{msg} = \text{sscheck}(A, B, C, D, K, X0) \]

**Description**
Check the dimensional consistency of the state space system:
\[
\begin{align*}
\dot{x}(t) &= Ax(t) + Bu(t) + Ke(t) \\
y(t) &= Cx(t) + Du(t) + e(t)
\end{align*}
\]
If the dimensions are consistent, `msg` is returned as the empty matrix, otherwise it will be returned as a string with an error message.

**See Also**
dds2ss
Purpose

Estimate a stochastic state space realization using Matrix Block Hankel factorization.

Synopsis

```matlab
dds = ssmbh(y,n)
dds = ssmbh(y,n,T,noscale)
```

Description

The parameters of the innovation state space system

\[ x(t_{k+1}) = Ax(t_k) + Ke(t_k) \]
\[ y(t_k) = Cx(t_k) + e(t_k) \]

are estimated using Matrix Block Hankel factorization, [1,2].

\( y \) is a matrix with the time series data of each channel stored columnwise. \( n \) is the desired state space dimension. The \( \text{dds} \) structure matrix is returned with the resulting parameter estimates.

The optional auxiliary arguments \( T \) and \( \text{noscale} \) are explained under `auxlsvar`.

See Also

`ddsstruc`, `na4sid`, `assem`

Reference


ss pem

Purpose
Prediction error estimate of an innovation state space realization.

Synopsis

dds=ss pem(y,ddsi)
dds=ss pem(y,ddsi,maxiter,tol,maxsize,T,lim,no covar,noscale,app)

Description
The parameters of a realization of the innovation state space system

\[
x(t_i) = Ax(t_i) + Bu(t_i) + Ke(t_i), \quad e(t_i) \sim NID(0, \Lambda)
\]

\[
y(t_i) = C x(t_i) + Du(t_i) + e(t_i)
\]

are estimated using a prediction error method, [1].

\( y \) is a matrix with the time series data of each channel stored columnwise. \( \text{ddsi} \) contains initial parameter estimates and structure information stored in a DDS structure. This structure is obtained as output from \( \text{initpem} \). The criterion minimization is then initialized at \( \text{ddsi} \). The DDS structure matrix is returned with the resulting parameter estimates, together with estimated covariance matrices.

The optional argument \( \text{app} \) is a string that controls which search-scheme to use. If \( \text{app} = 'GN' \) a Gauss-Newton search-scheme is applied. If \( \text{app} = 'ML' \) the search-scheme will be of the Marquardt-Levenberg type. The optional auxiliary arguments \( \text{maxiter}, \text{tol}, \text{maxsize}, T, \text{lim}, \text{no covar}, \text{noscale} \) are explained under auxvar.

Algorithm
If \( \text{app} = 'GN' \) a robustified quadratic prediction error criterion is minimized using an iterative damped Gauss-Newton algorithm. The Gauss-Newton vector is bisected up to ten times until a lower value of the criterion function is found. The iterations are terminated when \( \text{maxiter} \) is reached, when the Gauss-Newton search gradient has a norm less than \( \text{tol} \), or when a lower value of the criterion cannot be found.

If \( \text{app} = 'ML' \) the same robustified quadratic prediction error criterion is minimized using an iterative Marquardt-Levenberg algorithm. The iterations are terminated when \( \text{maxiter} \) is reached, when the Marquardt-Levenberg search gradient vector has a norm less than \( \text{tol} \), or when a lower value of the criterion cannot be found.

In order to obtain an initial guess of the parameters an initialization using a two-stage linear least-squares algorithm is used. This initialization is allowed to use ten iterations before terminating.
The cutoff value for the robustification is based on the parameter \( \text{lim} \) as well as on the estimated standard deviation of the residuals from the current parameter estimate. The returned loss function and innovation covariance matrix are the non-robustified ones.

A stability test of the predictor is performed to assure that only models corresponding to stable predictors are tested. Generally, the moving average matrix polynomial must have all its roots inside the unit circle.

Information about the minimization is furnished to the screen. Currently estimated parameters as well as values of the current and previous criterion functions are given. The norm of either the Gauss-Newton or the Marquardt-Levenberg search gradient is also displayed. The number in the upper left corner is the number of times the length of the search vector is adjusted. If configured for it, a graphical PEM Information Window will appear and present the information as well. This is controlled by the routine \text{initstdi}.

If configured for it, the routine will save all information about the identification after each iteration. In this way the currently obtained results are saved if a breakdown of the system should occur or if CRTL-C is hit. This is controlled by the routine \text{initstdi}. If the routine is stopped before completion, the data can be restored by the routine \text{tmp2dds}.

See Also

\text{armav}, \text{na4sid}, \text{auxlsvar}, \text{ddsstruc}, \text{tmp2dds}, \text{initstdi}

Reference

Purpose

Extract a submatrix from a row of matrices.

Synopsis

\[ \text{Asub} = \text{submat}(A, \text{indx}) \]
\[ \text{Asub} = \text{submat}(A, \text{indx}, \text{ncol}) \]

Description

\( A \) is a row of submatrices each with \( \text{ncol} \) columns. \( \text{Asub} \) is the submatrix number \( \text{indx} \) from the left of \( A \). All submatrices must have the same number of columns. If the submatrices are square, i.e., the number of columns of each of the submatrices are equal to the number of rows of \( A \), it is not necessary to specify \( \text{ncol} \).

Example

Consider a two-channel monic matrix polynomial \( \phi \) defined as

\[
\phi = \begin{bmatrix}
\text{eye}(2) & [1 \ 3; -5 \ 2] & [5 \ 8; 4 \ 2]\end{bmatrix}
\]

Extract the second polynomial coefficient as \( \text{Asub} \)

\[ \text{Asub} = \text{submat}(\phi, 2) \]
\[ \text{Asub} = \begin{bmatrix} 1 & 3 \\ -5 & 2 \end{bmatrix} \]

See Also

mat2vec, mporder, mpcheck
**Purpose**
Set the sampling interval in a DDS structure.

**Synopsis**
```plaintext
ddsnew = t2dds(dds, T)
```

**Description**
All functions that create the model descriptions in the DDS format sets the sampling period T in their last argument. For convenience `t2dds` offers an alternative to set it directly, i.e. `ddsnew` is equal to `dds` except that `ddsnew` is updated with T. If `dds` describes a continuous-time state space realization, and if for some purpose it is desirable to alter the default sampling period (T=1), the new sampling period must be supplied with a minus sign. This routine cannot be used for conversion between continuous-time and discrete-time systems.

**See Also**
`ddsstruc`, `dds2t`

Reference
*Structural Time Domain Identification Toolbox User's Guide*
### Purpose

Construct a DDS structure from a temporarily PEM backup file.

### Synopsis

```plaintext
dds = tmp2dds
```

### Description

If saving of temporarily backup files is enabled using `initstdi`, this routine will construct a DDS structure on the basis of the information stored in one of these files. Afterwards, the temporarily backup file will be deleted.

These particular backup files contain information about the status of the currently completed nonlinear PEM iteration of the routines `sspem` and `armav`. If a system failure or a CRTLC keyboard hit interrupt the optimization, this file will contain the necessary information needed in order to construct a DDS structure.

If backup files exist both for `sspem` and `armav` and if the information of both files is desired, this routine has to be called twice.

### See Also

`initstdi`, `armav`, `sspem`
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