

Identification with Stochastic Sampling Time Jitter[★]

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Abstract

This work investigates how stochastic sampling jitter noise affects the result of system identification, and proposes a modification of known approaches to mitigate the effects of sampling jitter, when the jitter is unknown and not measurable. By just assuming conventional additive measurement noise, the analysis shows that the identified model will get a bias in the transfer function amplitude that increases for higher frequencies. A frequency domain approach with a continuous time system model allows an analysis framework for sampling jitter noise. The bias and covariance in the frequency domain model are derived. This is used in bias compensated (weighted) least squares algorithms, and by asymptotic arguments this leads to a maximum likelihood algorithm. Continuous time output error models are used for numerical illustrations.

Key words: system identification, stochastic systems, least-squares estimation, maximum likelihood, frequency domain

1 Introduction

Consider a deterministic signal model $s(t; \theta)$, which may depend on an observed input. This work studies the problem of identifying the unknown parameter vector θ , when the discrete time observations y_k requested at time $t = kT$ (T denotes the sampling interval) are subject both to the usual additive measurement noise and also stochastic unmeasurable jitter noise τ_k as part of the sampling process. That is, the observation includes the term $s(kT + \tau_k; \theta)$, which becomes a stochastic variable.

This type of non uniform sampling may occur when uniform sampling is requested, but the sensor for one or several reasons cannot measure exactly at that time instant, and the true sampling time is either unmeasurable, or the communication protocol does not allow to transport time stamps to each measurement. Sampling jitter may also occur due to imperfect hold circuits, synchronization or other hardware problems. Not even high-performance digital oscilloscopes are free from sampling jitter as demonstrated in [16]. In [16], a dedicated system identification experiment is developed to estimate jitter

effects, and the result is that a commercial sampling oscilloscope with 1.22 ps sampling time has a sampling jitter standard deviation of around 1 ps, that is $\approx 80\%$ of the sampling time.

The general problem of nonuniform sampling is extensively treated in literature, see [1] and [10]. In most publications, the sampling times are known, and the problem is to analyze leakage and alias effects. Another twist is to design sampling times to minimize aliasing. For stochastic sampling jitter, the distribution of $s(t + \tau_k)$ is derived in [2, 3] and [15]. These results will be used and extended in this paper. In the context of jitter estimation, the sampling oscilloscope has been extensively studied, the methods include knowledge of the input signal, as in [17], and Taylor series expansions, in [16], in order to estimate the variance of the jitter and compensate for it. In this paper, we consider a model based approach, where the main goal is to find an underlying continuous system, and the jitter density can be seen as known or given in the estimation as a bi-product.

The basic idea is as follows. The frequency domain approach is to minimize the distance between the measurement and signal model Discrete Time Fourier Transforms (DTFT), $\|DTFT(y_k) - DTFT(s(kT + \tau_k; \theta))\|$ with respect to the parameters θ in some suitable norm. This frequency domain approach is standard in system identification [9, 12]. A continuous time model for $s(t)$ is used to be able to analyze the sampling jitter effects. The analysis shows that by neglecting the jitter, the Fourier Transform (FT) of the signal model will suffer

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from an amplitude bias in $|\text{FT}(s(t))| = |S(f)|$ that increases for higher frequencies. Further, the larger jitter noise variance, the larger bias. The remedy is to compensate for the bias, and the closed form solution involves a frequency weighting in the norm, $\|\text{DTFT}(y_k) - \int S(\psi)w(f, \psi)d\psi\|$.

The outline is as follows. The system identification problem and main notation are presented in Section 2. In Section 3, the bias effect of sampling jitter noise on the frequency transform is derived, and the bias compensated least squares estimator is proposed. Section 4 derives the second order properties of the frequency transform due to jitter noise, and a weighted least squares algorithm as well as an asymptotic maximum likelihood estimator are presented. Section 5 illustrates these algorithms for several simulated numerical examples. The work is concluded in Section 6.

2 Problem Formulation

The general problem formulation looks as follows. The sensor is requested to sample uniformly, but delivers discrete time measurements corrupted by amplitude noise and sampling time jitter according to

$$y_k = s(kT + \tau_k; \theta) + v(kT + \tau_k; \theta). \quad (1a)$$

The signal term, noise term and jitter distribution can all be dependent on the unknown parameter θ and given by

$$s(t; \theta) = (g_\theta \star u)(t), \quad (1b)$$

$$v(t; \theta) = (h_\theta \star e)(t), \quad (1c)$$

$$\tau_k \in p_\theta(\tau). \quad (1d)$$

Here $u(t)$ is a known input, $e(t)$ is white noise with known characteristics, $g_\theta(t)$ denotes the system impulse response and $h_\theta(t)$ the noise dynamics. The jitter sampling noise is a sequence of independent stochastic variables with probability density function (pdf) $p_\theta(\tau)$. Both the signal, noise and sampling models can be parameterized in the unknown parameter vector θ . We will primarily focus on continuous time systems here.

The system identification problems under consideration can be stated as estimating the parameter θ in a model structure

$$\mathcal{M}_{OE} : g_\theta(t), h_\theta(t) = \delta(t), p_\theta(\tau) = p(\tau), \quad (2a)$$

$$\mathcal{M}_{BJ} : g_\theta(t), h_\theta(t), p_\theta(\tau) = p(\tau), \quad (2b)$$

$$\mathcal{M}_{JOE} : g_\theta(t), h_\theta(t) = \delta(t), p_\theta(\tau), \quad (2c)$$

$$\mathcal{M}_{JBJ} : g_\theta(t), h_\theta(t), p_\theta(\tau). \quad (2d)$$

Here, OE denotes the output error and BJ the Box-Jenkins model structure, respectively, where the jitter

distribution is known. JOE and JBJ are the corresponding problems where also the jitter noise distribution is parametrized.

Using previous knowledge about the sampling jitter effect in the frequency domain indicates that the frequency domain approach, e.g., [9, 12], is suitable for identification in this case. Denote the Fourier transform of the measurements and signal model, respectively,

$$Y_d(f) = \sum_{k=0}^{N-1} y_k e^{-i2\pi f k T}, \quad (3)$$

$$S(f; \theta) = G(f; \theta)U(f). \quad (4)$$

The general problem formulation is now to minimize the distance between the measurement, $Y_d(f)$, and model, $S(f; \theta)$, in the frequency domain.

$$\hat{\theta} = \arg \min_{\theta} \int_{-\infty}^{\infty} \lambda(f; \theta) |Y_d(f) - S(f; \theta)|^2 df, \quad (5)$$

for some suitable weighting function. Normally, [9, 12], the weights, $\lambda(f; \theta)$ are given by the inverse noise spectrum. We will show a few other examples later.

Given a continuous signal model $S_c(f)$, a well known property of the Fourier transform gives that the discrete Fourier Transform, $S_d(f)$, becomes

$$S_d(f) = \int_{-\infty}^{\infty} S_c(\psi) d_N(f - \psi) d\psi. \quad (6)$$

Here $d_N(f)$ is the normalized Dirichlet kernel (also called the aliased sinc function), defined as

$$d_N(f) = e^{-i\pi f(N-1)T} \frac{\sin(\pi f NT)}{\sin(\pi f T)}. \quad (7)$$

The local behavior of the normalized Dirichlet kernel (see Fig. 1 on p. 4) describes the effects of leakage and its $1/T$ periodicity describes aliasing. For the regular case, with no sampling jitter, the correct way is to compare $Y_d(f)$ with $S_d(f; \theta)$, and using the unweighted least squares (LS) norm in (5) over a discrete set of frequencies yields the parameter vector θ as

$$\begin{aligned} \hat{\theta}^{\text{LS}} \\ = \arg \min_{\theta} \sum_f |Y_d(f) - \int_{-\infty}^{\infty} S_c(\psi; \theta) d_N(f - \psi) d\psi|^2. \end{aligned} \quad (8)$$

Similarly to [5, 13], the frequency set under consideration is arbitrary, in order to have the freedom to highlight certain frequency regions of interest.

This problem is closely related to the approach [6, 7] for the special case of no jitter noise, and [5] for the case of non-uniform sampling (but deterministic known sampling times). Note also that the leakage can also be interpreted as originating from a transient in the signal model caused by an unknown initial state. An alternative dual approach is based on estimating this initial state is studied in [12, 14].

The main idea with bias compensation is to mitigate the bias effects in $Y_d(f)$ by replacing the deterministic discrete time signal model $\int S_c(\psi; \theta) d_N(f - \psi) d\psi$ in (8) with a term, that besides sampling effects also includes the jitter noise. This term is denoted $\mu_Y(f)$, and is derived from $E(Y_d(f))$.

The purpose of this work is to analyze the bias and variance contribution from jitter sampling noise on the signal model $S_c(f; \theta)$, and modify the criterion (8) accordingly.

3 Bias Compensation

First, the bias in $Y_d(f)$ due to sampling jitter is derived. Then, the bias compensated LS (BCLS) estimate is defined. Equation (8) is here replaced by the more general expression

$$\hat{\theta} = \arg \min_{\theta} \sum_f |Y_d(f) - \mu_Y(f; \theta)|^2, \quad (9)$$

where $\mu_Y(f; \theta)$ is to be derived. In the following two subsections, the dependence on the parameter vector θ will be implicit.

3.1 Bias in $Y_d(f)$

The DTFT (3) of the sequence y_k using the sampling jitter model (1) can be written

$$\begin{aligned} Y_d(f) &= \sum_{k=0}^{N-1} y_k e^{-i2\pi f k T} \\ &= \sum_{k=0}^{N-1} (s(kT + \tau_k) + v_k) e^{-i2\pi f k T} \\ &= \hat{S}_d(f) + \underbrace{\sum_{k=0}^{N-1} v_k e^{-i2\pi f k T}}_{\hat{V}(f)}. \end{aligned} \quad (10)$$

Using the inverse FT $s(t) = \int_{-\infty}^{\infty} S_c(f) e^{i2\pi f t} dt$, the signal term becomes

$$\begin{aligned} \hat{S}_d(f) &= \sum_{k=0}^{N-1} s(kT + \tau_k) e^{-i2\pi f k T} \\ &= \sum_{k=0}^{N-1} \int_{-\infty}^{\infty} S_c(\psi) e^{i2\pi \psi (kT + \tau_k)} d\psi e^{-i2\pi f k T} \\ &= \int_{-\infty}^{\infty} S_c(\psi) W(f, \psi) d\psi, \end{aligned} \quad (11)$$

where

$$W(f, \psi) \triangleq \sum_{k=0}^{N-1} e^{i2\pi(\psi-f)kT} e^{i2\pi\psi\tau_k}. \quad (12)$$

The term W is a stochastic frequency window, completely describing the jitter, leakage *and* aliasing effects in the signal term $S_d(f)$ of $Y_d(f)$. Note that $W(f, \psi) = d_N(f - \psi)$ in the special case of no jitter, $\tau_k = 0$. It should be stressed that this continuous time frequency domain approach is perhaps the only way to explicitly separate the signal amplitude noise, captured in \hat{V} , and sampling jitter noise, captured in W , in a model-based setting.

3.2 First moment of W

The moments of the transform $Y_d(f)$ have an explicit dependence on the signal transform $S_c(f)$. The mean value of $Y_d(f)$ in (3) is

$$\begin{aligned} \mu_Y(f) &= E[Y_d(f)] = E[\hat{S}_d(f)] \\ &= \int_{-\infty}^{\infty} S_c(\psi) E[W(f, \psi)] d\psi \\ &= \int_{-\infty}^{\infty} S_c(\psi) \mu_W(f, \psi) d\psi \end{aligned} \quad (13)$$

and $\mu_W = E[W]$ is given by the following lemma.

Lemma 1 (Mean value) *The mean value, μ_W , with respect to τ_k , of the stochastic window, $W(f, \psi)$, defined in (12), is*

$$\mu_W(f, \psi) = \varphi(-\psi) d_N(f - \psi),$$

where $\varphi(f)$ is the characteristic function,² $\varphi(f) = E[e^{-i2\pi f \tau}]$, of τ and $d_N(f)$ is the normalized Dirichlet kernel (7).

² The usual definition from probability theory, $\varphi(u) = E[e^{iu\tau}]$, is slightly modified for notational convenience.

PROOF.

$$\begin{aligned}\mu_W(f, \psi) &= \mathbb{E}[W(f, \psi)], \\ &= \sum_{k=0}^{N-1} e^{i2\pi(\psi-f)kT} \mathbb{E}[e^{i2\pi\psi\tau_k}] \\ &= \varphi(-\psi) \underbrace{\frac{1 - e^{i2\pi(\psi-f)NT}}{1 - e^{i2\pi(\psi-f)T}}}_{d_N(f-\psi)},\end{aligned}$$

where we recognize the characteristic function, $\varphi(f) = \mathbb{E}[e^{-i2\pi f\tau}]$ and the normalized Dirichlet kernel, d_N .

The characteristic function $\varphi(f) = \varphi(f; \theta)$ models damping corresponding to the sampling jitter noise. It will include possible distribution parameters from $p_\theta(\tau)$ in (2). Its properties include, see e.g., [11]:

- The definition gives, $|\varphi(f)| \leq \varphi(0) = 1, \forall f$.
- From the series expansion we know that if $\varphi(f) = 1$, for all f , all moments $\mathbb{E}[(\tau_k)^n] = 0$, so there is no jitter noise,
- For zero-mean jitter, the decay rate of $|\varphi(f)|$ increases with the jitter noise variance, for a given class of distributions, also given by the series expansion.

The second property implies that $\mu_W(f, \psi) = d_N(f - \psi)$ for the case of no jitter noise.

3.3 Bias Compensated Least Squares Estimate

Since now $\mu_Y(f) = \mathbb{E}[Y_d(f)]$ is completely known, we can compensate for both the leakage and jitter effect on the measurement DTFT. We include this in the parameter estimation as, cf. (9),

$$\hat{\theta}^{\text{BCLS}} = \arg \min_{\theta} \sum_f |Y_d(f) - \mu_Y(f; \theta)|^2 \quad (14a)$$

where

$$\mu_Y(f; \theta) = \int_{-\infty}^{\infty} S_c(\psi; \theta) \varphi(-\psi; \theta) d_N(f - \psi) d\psi. \quad (14b)$$

Both the signal $S_c(f; \theta)$ and jitter pdf $p(\tau; \theta)$, and thus characteristic function $\varphi(f; \theta)$, may depend on the unknown parameter vector θ .

3.4 Illustrations

Let us consider the implications of Lemma 1 in more detail. The Dirichlet kernel that appears as the window function in the jitter-free case is illustrated in Fig. 1

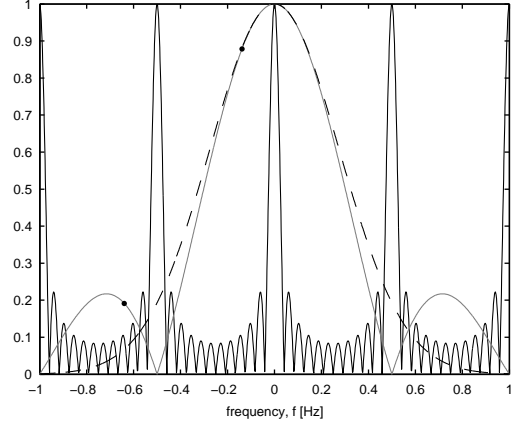


Fig. 1. Example of the normalized Dirichlet kernel, $d_N(f)$ (solid black), (7), and the two characteristic functions, $\varphi_\tau(f)$ in (15), (a) solid gray and (b) dashed.

(solid black). As two concrete examples of characteristic functions, consider

$$\tau \in U(-1, 1) \quad \Rightarrow \quad \varphi(f) = \frac{\sin(2\pi f)}{2\pi f} \quad (15a)$$

$$\tau \in N(0, 1/3) \quad \Rightarrow \quad \varphi(f) = e^{-2\pi^2 f^2/3}, \quad (15b)$$

which have the same variance. The amplitudes of these functions are also illustrated in Fig. 1.

According to Lemma 1, the jitter noise will attenuate the amplitude of $Y_d(f)$. The attenuation is inversely linear in frequency for uniform jitter and exponentially decaying for Gaussian jitter noise. This also implies that frequencies above the Nyquist frequency are attenuated, suppressing alias. This attenuation is compensated for in the BCLS estimate.

Consider now a single frequency signal with known amplitude and phase, but unknown frequency, f_0 , $s(t) = \sin(2\pi f_0 t)$, such that $S_c(f) = 1/2i(\delta(f - f_0) - \delta(f + f_0))$. We compare uniform sampling, $T = 2$, and jitter sampling, $\tau \in U(-T/2, T/2)$, for two different frequencies f_0 , and get the following expressions on the positive frequency axis. Uniform sampling gives

$$Y_d(f) = \frac{1}{2i} d_N(f - 0.14), \quad f_0 = 0.14 \quad (16a)$$

$$Y_d(f) = \frac{1}{2i} d_N(f - 0.64), \quad f_0 = 0.64, \quad (16b)$$

where $d_N(f - 0.14) = d_N(f - 0.64)$. When the sampling times are corrupted by jitter noise, (13) and Lemma 1

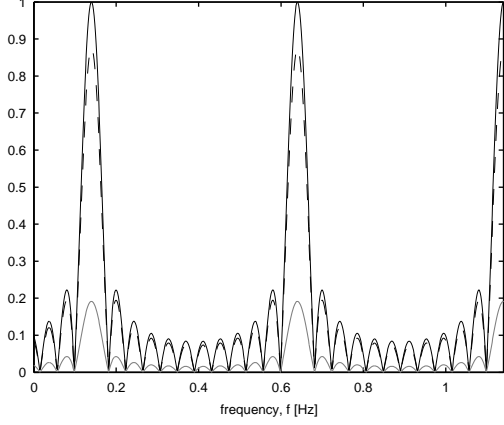


Fig. 2. $|E[Y_d(f)]|$ given in (16) are shown, (a) and (b) (thin line) overlap, while (c) (dashed) and (d) (thick gray) are different. The sampling jitter noise in the last two cases is given by (15a), and the damping could be find directly by studying $\varphi_\tau(f)$ in Fig. 1, note the two dots.

give

$$E[Y_d(f)] = \frac{1}{2i}\varphi(-0.14)d_N(f - 0.14), \quad f_0 = 0.14 \quad (16c)$$

$$E[Y_d(f)] = \frac{1}{2i}\varphi(-0.64)d_N(f - 0.64), \quad f_0 = 0.64. \quad (16d)$$

The result is still periodic, but with different damping depending on the frequency.

This is also shown in Fig. 2, where $|Y_d(f)|$ and $|E[Y_d(f)]|$ are plotted for the different cases in (16). The sampling jitter noise is given by (15a). From Fig. 1, we know that the amplitude bias is larger for higher frequencies f_0 , $0 < \varphi(-0.64) < \varphi(-0.14) < 1$, which is why we can separate the two frequencies in this jitter sampling case.

4 Covariance Compensation

Bias compensating $Y_d(f)$ implies unbiased estimates of $S_c(f; \theta)$. To reach asymptotic efficiency, also the variance of $Y_d(f)$ is needed. In this section, both a Weighted Least Squares (WLS) and Maximum Likelihood (ML) estimates are stated based on this covariance.

4.1 Covariance of $Y_d(f)$

To use these two estimators we need the covariance of Y , R_Y , which we get from the expressions in (10) as

$$R_Y(f, \psi) = R_{\hat{S}}(f, \psi) + R_{\hat{V}}(f, \psi), \quad (17)$$

with

$$\begin{aligned} R_{\hat{S}}(f, \psi) &= \text{Cov}(\hat{S}(f), \hat{S}(\psi)) \\ &= \iint S(\eta) \text{Cov}(W(f, \eta), W(\psi, \zeta)) S(\zeta)^* d\eta d\zeta, \\ &= \iint S(\eta) R_W(f, \eta, \psi, \zeta) S(\zeta)^* d\eta d\zeta. \end{aligned} \quad (18)$$

Here, $R_W(f, \eta, \psi, \zeta) \triangleq \text{Cov}(W(f, \eta), W(\psi, \zeta))$ is the covariance of the stochastic frequency window in (12). The contribution from the measurement noise is

$$\begin{aligned} R_{\hat{V}}(f, \psi) &= \text{Cov}(\hat{V}(f), \hat{V}(\psi)), \\ &= \sigma^2 \sum_{k=0}^{N-1} e^{-i2\pi(f-\psi)kT}, \end{aligned}$$

since we restricted the investigation to white Gaussian measurement noise.

4.2 Covariance of $W(f)$

The covariance of $W(f)$ is

$$\begin{aligned} R_W(f, \eta, \psi, \zeta) &= E[W(f, \eta)W^*(\psi, \zeta)] - \mu_W(f, \eta)\mu_W(\psi, \zeta)^* \end{aligned} \quad (19)$$

and the second order moment is given by the following lemma.

Lemma 2 (Second order moment) *The second order moment of W is given as*

$$E[W(f, \eta)W^*(\psi, \zeta)] = \Phi^T(\eta, \zeta)D_N(f - \eta, \psi - \zeta).$$

where

$$\Phi(f, \psi) = \begin{pmatrix} \varphi(-f)\varphi(\psi) \\ \varphi(\psi - f) \\ \varphi(-f)\varphi(\psi) \end{pmatrix}$$

and

$$D_N(f, \psi) = \begin{pmatrix} \sum_{k=0}^{N-1} \sum_{l=0}^{k-1} e^{-i2\pi(fk-\psi l)T} \\ d_N(f - \psi) \\ \sum_{k=0}^{N-1} \sum_{l=0}^{k-1} e^{-i2\pi(-\psi k + fl)T} \end{pmatrix}.$$

The functions were defined in Lemma 1

PROOF. The second moment of the stochastic window, W , is by definition

$$\begin{aligned} E[W(f, \eta)W^*(\psi, \zeta)] &= \sum_{k,l} e^{i2\pi(\eta-f)kT} E[e^{i2\pi(\eta\tau_k - \zeta\tau_l)}] e^{-i2\pi(\zeta-\psi)lT} \\ &= \sum_k \sum_{l < k} + \sum_k \sum_{l=k} + \sum_k \sum_{l > k} \\ &= V_1 + V_2 + V_3. \end{aligned}$$

The first term of the second moment above is

$$\begin{aligned} V_1(f, \psi, \eta, \zeta) &= \varphi(-\eta)\varphi(\zeta) \sum_{k=0}^{N-1} e^{i2\pi(\eta-f)kT} \sum_{l=0}^{k-1} e^{-i2\pi(\zeta-\psi)lT} \end{aligned}$$

since $\varphi(f) = E[e^{-i2\pi f\tau_k}]$ was the CF of τ_k and τ_k are i.i.d. The second term is the sum over $l = k$,

$$\begin{aligned} V_2(f, \psi, \eta, \zeta) &= \sum_{k=0}^{N-1} e^{i2\pi(\eta-f-\zeta+\psi)kT} \varphi(\zeta - \eta) \\ &= \varphi(\zeta - \eta) d_N(f - \eta - \psi + \zeta) \end{aligned}$$

and, finally, the third term is

$$\begin{aligned} V_3(f, \psi, \eta, \zeta) &= \varphi(-\eta)\varphi(\zeta) \sum_{l=0}^{N-1} e^{-i2\pi(\zeta-\psi)lT} \sum_{k=0}^{l-1} e^{i2\pi(\eta-f)kT} \end{aligned}$$

Identification of terms gives the result of the Lemma.

The two factors, Φ and D_N , correspond to parts depending on the sampling noise and on the finite sampling, respectively, cf. $\varphi(f)$ and $d_N(f)$ in Lemma 1. It is also quite straightforward to verify $R_W(f, \eta, \psi, \zeta) = 0$ when there is no sampling jitter present, since in that case, $E[W(f, \eta)W^*(\psi, \zeta)] = d_N(f - \eta)d_N(\psi - \zeta)^* = \mu_W(f, \eta)\mu_W(\psi, \zeta)^*$, and (19) evaluates to zero.

4.3 Weighted Least Squares

The jitter noise will perturb higher frequencies more than lower frequencies, which can be mitigated with the Weighted Least Squares (WLS) approach, see e.g., [8, Ch. 2], where the weights, $\lambda(f)$, are given by the covariance. Furthermore, the correlation between different frequencies needs to be taken into account. That is, (9) is here extended to

$$\begin{aligned} \hat{\theta}^{\text{WBCLS}} &= \arg \min_{\theta} \left\{ (Y - \mu_Y(\theta))^* R_Y(\theta)^{-1} (Y - \mu_Y(\theta)) \right\}, \end{aligned} \quad (20)$$

where $R_Y = I$ corresponds to (9). Here $Y = (Y_d(f_1), \dots, Y_d(f_n))^T$, $\mu_Y = E[Y]$ from (13) and Lemma 1, and $R_Y = \text{Cov}(Y)$ as given in (17), (19) and Lemma 2.

4.4 Maximum Likelihood

The central limit theorem together with the fact that the sampling noise τ_k and the measurement noise v_k are i.i.d., Equations (10) and (11) indicate that both \hat{V} and \hat{S}_d are asymptotically Gaussian, and hence

$$Y_d \in \text{AsN}(\mu_Y, R_Y), \quad (21)$$

where AsN denotes the asymptotic Gaussian distribution. When this holds, the asymptotic Maximum Likelihood (ML) estimator, see e.g., [9, Ch. 7] or [4], can be defined as

$$\begin{aligned} \hat{\theta}^{\text{AsML}} &= \arg \min_{\theta} \left\{ (Y - \mu_Y(\theta))^* R_Y(\theta)^{-1} (Y - \mu_Y(\theta)) + \ln \det R_Y(\theta) \right\}, \end{aligned} \quad (22)$$

with the vector Y , the mean μ_Y and variance R_Y given in the previous section.

4.5 Implementation issues

In the examples in Sec. 5, a grid based search is implemented to avoid problems with local minima. However, a promising alternative would be to use numerical methods to minimize the estimators in (20) and (22), like gradient or Gauss-Newton searches as described in [9]. To avoid potential problems with local minima, the parameter vector can be initialized by standard methods for OE models [9] neglecting the jitter noise. This should work fine for moderate levels of jitter noise.

One way to avoid the matrix inversion of R_Y is to only consider frequencies $f = n/NT$ for integer valued n . The idea is that the Fourier transform $Y_d(f)$ is asymptotically uncorrelated [9] for these frequencies, which would simplify the estimators considerably. For instance, the asymptotic ML estimator from (22) becomes

$$\begin{aligned} \hat{\theta}^{\text{AsML}} &= \arg \min_{\theta} \sum_n \left\{ \frac{|Y_d(n/NT) - \mu_Y(n/NT; \theta)|^2}{R_Y(n/NT; \theta)} + \ln R_Y(n/NT; \theta) \right\}. \end{aligned} \quad (23)$$

5 Examples

Three numerical examples are presented. First, a known first order OE model is used to illustrate that the jitter

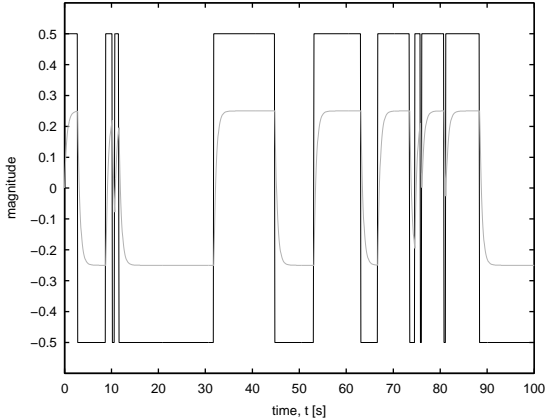


Fig. 3. Example of a PRBS signal ($u(t)$ black) and the output from $G(s) = 1/(s + 2)$, ($s(t)$ gray), in continuous time.

noise distribution is identifiable. Then, a \mathcal{M}_{OE} and a \mathcal{M}_{JOE} example, both with second order systems, are presented to illustrate the main results.

To find the best parameter vector θ the maximum likelihood estimator (22) will be used. The DTFT is calculated for the frequencies $f_k = k/NT$, $k = 0, \dots, \lfloor N/2 \rfloor - 1$, i.e., we get the DFT. In the examples we will also use the least squares estimator (14) to compare with.

The input $u(t)$ is a Pseudo Random Binary Sequence (PRBS) signal, which jumps between -0.5 and 0.5 at time intervals of exponentially distributed lengths, with a mean value of 1 s. The measurement noise $v(t)$ is zero-mean Gaussian with standard deviation 0.01.

5.1 Known first order OE model with unknown jitter pdf

For this example we chose

$$\mathcal{M} : g_\theta(t) = \mathcal{L}^{-1} \left(\frac{1}{s + 2} \right), h_\theta(t) = \delta(t), p_\theta(\tau), \quad (24)$$

where \mathcal{L} denotes the Laplace Transform operator. Here only $p_\theta(t)$ is parameter dependent, and the system is known. We use a known first order system, where the input and measurement noise were defined above. In Fig. 3, an example of the input $u(t)$ and output $y(t)$ is given for the above settings.

The focus is on finding the distribution of the sampling noise. We choose a parameterization based on a sum of $n + 1$ uniformly distributed variables in the interval $[-a/(n + 1), a/(n + 1)]$. That is, the support of the pdf $p_\theta(\tau)$ is $[-a, a]$, and its parameters are $\theta = (n, a)^T$. The

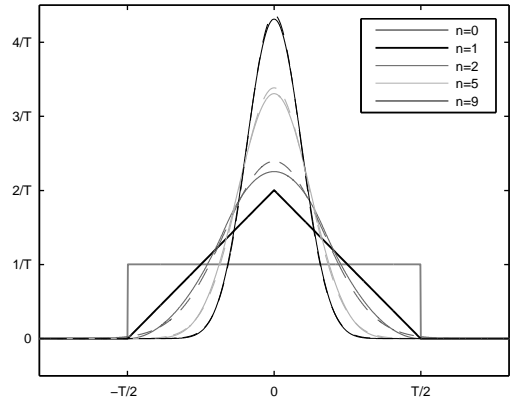


Fig. 4. The solid lines show the pdf, $p_\theta(\tau)$, corresponding to different values of $\theta = (n, T/2)^T$, when the CF is $\varphi(f) = \text{sinc}(\frac{fT}{n+1})^{n+1}$. For the higher values of n , the dashed lines show the Gaussian bells with the same variance as the parameterized pdf. The difference is almost invisible in this plot for $n = 9$.

characteristic function of $p_\theta(\tau)$ can be written as

$$\varphi_\theta(f) = \left(\frac{\sin(\frac{2\pi fa}{n+1})}{\frac{2\pi fa}{n+1}} \right)^{n+1} = \text{sinc} \left(\frac{2fa}{n+1} \right)^{n+1}, \quad (25)$$

since a sum of independent stochastic variables corresponds to convolving their pdf's, which in turns corresponds to multiplying their characteristic functions. The expected value is 0 and the variance is $\sigma^2 = \frac{1}{n+1} \frac{a^2}{3}$. Setting $n = 0$ yields a rectangular distribution, $n = 1$ a triangular distribution, and increasing n makes the distribution converge to a normal distribution, with decreasing variance. Thus, a higher n indicates a more narrow distribution. See Fig. 4 for a few examples of the pdf and corresponding (of equal variance) Gaussian distribution.

Now, we want to test both jitter covering the whole interval $[-T/2, T/2]$, as well as only a portion of it; change the order but keep the variance fixed; and also look outside the model class. Therefore, we use $p_\theta(\tau)$ given by the CF in (25), for four sets of true parameters $[n^0, a^0] = [0, T/2], [0, T/2\sqrt{3}], [2, T/2],$ and $[2, T/2\sqrt{3}]$, with sampling time $T = 1$. This gives the variance of the jitter as $(\sigma^0)^2 = (T/2\sqrt{3})^2, (T/6)^2, (T/6)^2$ and $(T/6\sqrt{3})^2$, respectively. We also let the true pdf be a zero-mean Gaussian distribution with the same variance as the two last cases above, namely $\sigma^2 = (T/6)^2$ and $\sigma^2 = (T/6\sqrt{3})^2$.

The identification procedure now follows:

- The mean value $\mu_Y(f)$ is given by (13) and Lemma 1, together with the model specifications given in (24) and (25).

Table 1

Results for identification of model (24). Mean value and standard deviation of $\hat{\theta} = (\hat{n} \hat{a})^T$ and $\hat{\sigma} = \hat{a}/\sqrt{3(\hat{n} + 1)}$ for six sets of true parameters, θ^0 . In each of the six blocks, the top row shows the true parameter values. The following two rows are the results for BCLS estimation, mean value and standard deviation. The last two rows are the corresponding results for ML estimation. The two lowest blocks have true pdf's outside the model class, which is why no true values of n and a are given.

	n	a	σ	n	a	σ
θ^0	0	0.5	$1/\sqrt{12} \approx 0.2887$	0	$1/\sqrt{12} \approx 0.2887$	$1/6 \approx 0.1667$
$E[\hat{\theta}^{\text{BCLS}}]$	0.2145	0.4683	0.2599	1.1818	0.3759	0.1682
$\text{Std}[\hat{\theta}^{\text{BCLS}}]$	0.7360	0.0678	0.0489	1.6815	0.1186	0.0649
$E[\hat{\theta}^{\text{AsML}}]$	0.0437	0.4801	0.2719	0.7073	0.3660	0.1671
$\text{Std}[\hat{\theta}^{\text{AsML}}]$	0.0789	0.0233	0.0170	0.8184	0.0662	0.0224
θ^0	2	0.5	$1/6 \approx 0.1667$	2	$1/\sqrt{12} \approx 0.2887$	$1/(6\sqrt{3}) \approx 0.0962$
$E[\hat{\theta}^{\text{BCLS}}]$	1.1386	0.3752	0.1676	1.6816	0.2618	0.1018
$\text{Std}[\hat{\theta}^{\text{BCLS}}]$	1.6608	0.1088	0.0592	1.9972	0.1553	0.0607
$E[\hat{\theta}^{\text{AsML}}]$	0.6420	0.3766	0.1732	2.4947	0.3015	0.1011
$\text{Std}[\hat{\theta}^{\text{AsML}}]$	0.6439	0.0753	0.0250	2.1080	0.0866	0.0205
θ^0	—	—	$1/6 \approx 0.1667$	—	—	$1/(6\sqrt{3}) \approx 0.0962$
$E[\hat{\theta}^{\text{BCLS}}]$	1.8175	0.3267	0.1281	1.8807	0.1958	0.0752
$\text{Std}[\hat{\theta}^{\text{BCLS}}]$	2.0357	0.1607	0.0678	2.1966	0.1425	0.0530
$E[\hat{\theta}^{\text{AsML}}]$	1.0115	0.3589	0.1515	3.4188	0.2696	0.0802
$\text{Std}[\hat{\theta}^{\text{AsML}}]$	1.0415	0.0855	0.0297	2.4361	0.0877	0.0219

- The covariance, R_Y , can be deduced from Lemma 2.
- The parameter estimates, $\hat{\theta}$, are given from (14) for the BCLS estimate and from (22) for the asymptotic ML estimate.
- After minimization, an estimate of the standard deviation is given by $\hat{\sigma} = \hat{a}/\sqrt{3(\hat{n} + 1)}$ for each run.

For the six different pdf's, we evaluate the mean value and the standard deviation of the estimated parameters, $\hat{\theta}$, based on 128 different realizations of the sampling noise sequence and the input. The result is shown in Table 1, for both the ML and BCLS estimate, using the model in (24). We also compute the estimate of the standard deviation σ , implied by \hat{n} and \hat{a} . We can conclude the following:

- The standard deviation σ for the sampling noise is accurately estimated, while the exact parameter constellation, $(n \ a)^T$, is harder. This can be due to too few samples ($N = 200$) to be able to estimate the shape of the distribution.
- The distribution with $n^0 = 0$, $a^0 = 0.5$, rectangular over the whole interval, has best results.
- The ML estimate has the smallest error for all cases, indicating that the covariance R_Y vary significantly along the frequency axis.
- True pdf's outside the model class (last two tests) pose no problem to the estimation of σ .

Despite the small number of measurements, the estima-

tion of the jitter noise covariance works nice. Comparing with earlier results were this was the final goal [16, 17], we are satisfied, and continue with the focus of this work, model estimation. The results here are promising for further investigation, when jitter noise properties are sought.

5.2 Unknown second order OE model with known jitter pdf

Now, let us focus on the linear system, $g(t)$, that is, the \mathcal{M}_{OE} problem in (2a). We illustrate the algorithms for a second order system, specified by its transfer function G . The model is

$$\mathcal{M} : g_\theta(t), h_\theta(t) = \delta(t), p_\theta(\tau) = p(\tau). \quad (26a)$$

The system $g_\theta(t) = \mathcal{L}^{-1}(G_\theta(s))$ is parameterized as

$$G_\theta(s) = \frac{k_0}{(s - (p_r + ip_i))(s - (p_r - ip_i))} \quad (26b)$$

$$\theta = (k_0 \ p_r \ p_i)^T \quad (26c)$$

with the true parameters being $\theta^0 = (6.25, -1.5, 2)^T$ during this run. The sampling noise distribution, $p(\tau)$, is known and given by (25) with $n = 0$ and $a = T/2$. The input and measurement noise are the same as in Sec. 5.1.

Table 2

Results for identification of model (26). Mean value and standard deviation of $\hat{\theta} = (\hat{k}_0 \hat{z} \hat{p}_r \hat{p}_i)^T$ for the three estimates given by (8), (14) and (22).

Model (26)	k_0	p_r	p_j
θ^0	6.25	-1.5	2
$E[\hat{\theta}^{\text{LS}}]$	5.8468	-1.5876	1.9508
$\text{Std}[\hat{\theta}^{\text{LS}}]$	0.1723	0.0448	0.0045
$E[\hat{\theta}^{\text{BCLS}}]$	6.2536	-1.4981	2.0019
$\text{Std}[\hat{\theta}^{\text{BCLS}}]$	0.0479	0.0385	0.0415
$E[\hat{\theta}^{\text{AsML}}]$	6.2499	-1.5008	2.0000
$\text{Std}[\hat{\theta}^{\text{AsML}}]$	0.0480	0.0343	0.0401

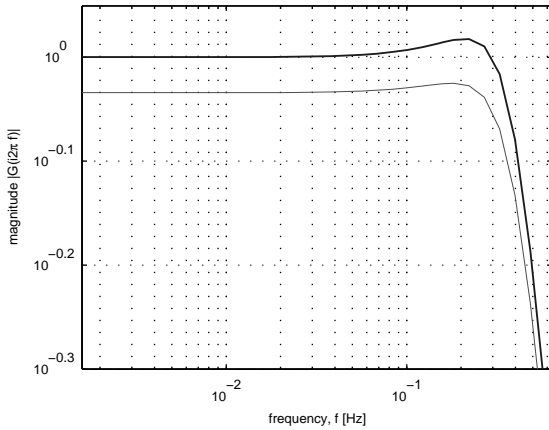


Fig. 5. A comparison of $|G_\theta(i2\pi f)|$ (thin line), given by (26) and $\theta = E[\hat{\theta}^{\text{LS}}]$ from Table 2, with the true $|G_{\theta^0}(i2\pi f)|$ (thick line). When using $\hat{\theta}^{\text{BCLS}}$ or $\hat{\theta}^{\text{AsML}}$ the difference from the true system is not visible.

The parameters are now given by the same identification procedure as described on p. 7. The result for the ML and BCLS estimation is shown in Table 2. We also compare with the results when no bias-compensation is used (LS in (8))

- Estimates from BCLS and AsML are unbiased with small estimate variances ($> 2\%$).
- The difference between BCLS and AsML are not as obvious as in the former identification setup, although all parameters are estimated slightly better.
- As has been seen before, in both analysis, and previous investigations, the LS estimate introduces a significant bias.

This is more visible when studying the magnitude of the identified system. Figure 5 shows $|G_\theta(i2\pi f)|$ with $\theta = E[\hat{\theta}^{\text{LS}}]$ compared to $|G_{\theta^0}(i2\pi f)|$. Using the parameters from LS or AsML does not give a visible difference from the true system.

5.3 Unknown second order OE model with unknown jitter pdf

The previous example is extended by letting the jitter noise pdf be unknown. That is, consider the \mathcal{M}_{JOE} problem in (2c). The system $g_\theta(t)$ is given by (26) and the sampling noise pdf, $p_\theta(\tau)$, is given by (25), with $\theta = (n \ a \ k_0 \ p_r \ p_i)^T$ and the true parameters being $\theta^0 = (2, T/2\sqrt{3}, 6.25, -1.5, 2)^T$. The input and measurement noise are the same as in Sec. 5.1.

From the two previous sections, we know that n and a were hard to estimate, whereas k_0 , z , p_r and p_j posed no problem. We expect to see similar things for the joint problem. The parameters are now given by the same identification procedure as described on p. 7. The chosen parametrization enables full separation of the dynamic model and the jitter noise, since the true system, $S_c(f)$, is only multiplied by the CF of the jitter noise, $\varphi(f)$, and not mixed.

The identification results are given in Table 3. The two estimates are good for all parameters. The AsML estimate performs better for the probability density parameters, especially n , where the BCLS estimate has higher variance. It is interesting to note that the result is better for estimating n and a than for the corresponding pdf when the system was known, Section 5.1. Both here and in the previous section the reduced AsML estimate (23) was used, for computational reasons.

6 Conclusions

The stochastic jitter noise in the model $y_k = s(kT + \tau_k; \theta) + v_k$ should not be neglected and included in the measurement noise v_k . The bias compensated least squares estimator describes both the effects of jitter and the remedy:

$$\hat{\theta}^{\text{BCLS}} = \arg \min_{\theta} \sum_f |Y_d(f) - \int_{-\infty}^{\infty} S(\psi; \theta) \varphi(-\psi; \theta) d_N(f - \psi) d\psi|^2.$$

This criteria minimizes the LS distance between measurement DTFT and the model's FT, taking leakage and alias effects into account via a convolution with the normalized Dirichlet kernel $d_N(f - \psi)$. The characteristic function $\varphi(-\psi; \theta)$ of the jitter noise implies a scaling of the signal model $S_c(f)$. By neglecting this, a bias in the estimation would result.

A second order compensation of jitter effects leads to the WLS estimator (20) and the asymptotic maximum likelihood estimator (22). The estimators were illustrated on simulated examples for continuous time OE system

Table 3

Mean value and standard deviation of $\hat{\theta} = (\hat{n} \hat{a} \hat{k}_0 \hat{z} \hat{p}_r \hat{p}_i)^T$ in the model (26) with jitter noise as defined in (25).

Model (25),(26)	n	a	k_0	p_r	p_j	σ
θ^0	2	$\frac{T}{2\sqrt{3}} \approx 0.2887$	6.25	-1.5	2	$1/(6\sqrt{3}) \approx 0.0962$
E[$\hat{\theta}^{\text{BCLS}}$]	1.8281	0.2960	6.2609	-1.4980	2.0044	0.1061
Std[$\hat{\theta}^{\text{BCLS}}$]	1.0357	0.0324	0.0331	0.0262	0.0289	0.0179
E[$\hat{\theta}^{\text{ASML}}$]	2.2578	0.2918	6.2513	-1.5045	1.9964	0.0947
Std[$\hat{\theta}^{\text{ASML}}$]	0.8534	0.0329	0.0334	0.0221	0.0278	0.0072

identification, with known or with parametrized jitter distribution. The results are very promising and a clear motivation to develop dedicated algorithms for the case of jitter noise. For example, efficient Gauss-Newton algorithms would be useful, where also unknown noise models (Box-Jenkins structures) could be targeted.

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