Robust Estimation of the Spectral Density Function with Applications to the Analysis of Heart Rate Variability

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Motivation

Spectral estimation in

• geophysics

 \bullet signal processing

 \bullet medicine \rightarrow analysis of heart rate variability (HRV) as noninvasive method

Data Model with Additive Outliers (AO)

The process $\{y_t : t \in \mathbb{Z}\}$ is said to have additive outliers (AO) if it is defined by

 $y_t = x_t + v_t$

where x_t is an ARMA(p, q) process and the v_t are independent, identically distributed (iid) with $F_v = (1 - \varepsilon)\delta_0 + \varepsilon H$ where δ_0 is the degenerated distribution having all its mass at the origin and H is a heavy-tailed symmetric distribution with mean 0 and variance σ_H^2 .

Simulated Data

Consider the artificial process with AO composed of the following three autoregressive processes (Kleiner et al., 1979):

 $u_k = 0.975u_{k-1} + \varepsilon_k ,$ $w_k = 0.95w_{k-1} - 0.9w_{k-2} + \eta_k ,$ $z_k = 0.33z_{k-1} - 0.9z_{k-2} + \zeta_k ,$

with $\varepsilon_k, \eta_k, \zeta_k \sim N(0, 1)$. u_k, w_k and z_k are standardized and

 $y_k = \sqrt{75}u_k + w_k + z_k , \quad k = 1, \dots, n ,$

is computed. y_k is standardized again. Additionally, noise from $0.9\delta_0 + 0.1N(0, 100)$ is added.

Simulated Process Without Outliers

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Heart Rate Variability Data

- Real data: heart rate variability (HRV) recordings (tachogram of 1321 successive heart beats)
- provided by J. Pumprla and K. Howorka, Department of Biomedical Engineering and Physics, General Hospital of Vienna

Original Tachogram

Robust Filter-cleaner

Let $\{y_k, k = 1, ..., N\}$ denote the observed values of a second-order stationary process with mean zero. The filter-cleaner algorithm (cf. Martin and Thomson, 1982) relies on the AR(p) approximation of the underlying process x_t , represented in the following state-space form with t = p + 1, ..., N:

 $\boldsymbol{X}_t = \boldsymbol{\Phi} \boldsymbol{X}_{t-1} + \boldsymbol{U}_t \; ,$

where

 $\boldsymbol{X}_t = (x_t, x_{t-1}, \dots, x_{t-p+1})^\top , \\ \boldsymbol{U}_t = (\varepsilon_t, 0, \dots, 0)^\top ,$

with
$$\mathbf{\Phi} = \begin{pmatrix} \phi_{1,p} \cdots \phi_{p-1,p} & \phi_{p,p} \\ 1 & \cdots & 0 & 0 \\ \vdots & \ddots & \vdots & \vdots \\ 0 & \cdots & 1 & 0 \end{pmatrix}$$
, $\operatorname{cov}(\mathbf{U}_t) = \mathbf{Q} = \begin{pmatrix} \sigma_{\varepsilon,p}^2 & 0 \cdots & 0 \\ 0 & 0 & \cdots & 0 \\ \vdots & \vdots & \ddots & \vdots \\ 0 & 0 & \cdots & 0 \end{pmatrix}$ and

 $y_t = x_t + v_t = (1, 0, \dots, 0) \mathbf{X}_t + v_t$ with $var(v_t) = \sigma_0^2$.

The algorithm computes robust estimates \widehat{X}_t of the unobservable X_t according to the following recursion:

$$\widehat{\boldsymbol{X}}_t = \boldsymbol{\Phi} \widehat{\boldsymbol{X}}_{t-1} + rac{\boldsymbol{m}_t}{s_t^2} s_t \ \psi\left(rac{y_t - \hat{y}_t^{t-1}}{s_t}
ight)$$

with \boldsymbol{m}_t being the first column of \boldsymbol{M}_t , which is computed recursively as

$$oldsymbol{M}_{t+1} = oldsymbol{\Phi} oldsymbol{P}_t oldsymbol{Q}_t oldsymbol{P}_t = oldsymbol{M}_t - w \left(rac{y_t - \hat{y}_t^{t-1}}{s_t}
ight) rac{oldsymbol{m}_t oldsymbol{m}_t^ op}{s_t^2} \,.$$



The weight function $w(r) = \psi(r)/r$ where ψ stands for some robustifying function. The scale s_t is defined by $s_t^2 = m_{11,t}$ and \hat{y}_t^{t-1} denotes a robust one-step prediction of y_t based on $\mathbf{Y}^{t-1} = (y_1, \ldots, y_{t-1})^{\top}$, and is given by

$$\hat{y}_t^{t-1} = (\boldsymbol{\Phi}\widehat{\boldsymbol{X}}_{t-1})_1$$

Finally, the cleaned process at time t results in

$$\hat{x}_t = (\widehat{\boldsymbol{X}}_t)_1$$

To use the filter-cleaner algorithm we need robust estimates $\hat{\phi}_p$ and $\hat{\sigma}_{\varepsilon,p}^2 = s_{\varepsilon,p}^2$ of $\phi_p = (\phi_{1,p}, \dots, \phi_{p,p})^{\top}$ and $\sigma_{\varepsilon,p}^2$.

Different approaches to obtain initial estimates lead to similar results, namely

- using bounded-influence autoregression (BIAR) via iteratively reweighted least squares (IWLS) (cf. Martin and Thomson, 1982)
- a highly robust autocovariance function estimator (cf. Ma and Genton, 2000) and the Yule-Walker equations
- robust autoregression using LTS- and LMS-regression

Robust Spectral Estimation via WOSA

WOSA stands for Welch's Overlapped Segment Averaging.
Let y_t, t = 1,..., N, be the observed process.
Split the process into N_B overlapping blocks of length N_S.
Calculate direct spectral estimates for different blocks of N_S contiguous data values

$$\widehat{S}_{l}^{(d)}(f) = \Delta t \left| \sum_{t=1}^{N_{S}} h_{t} y_{t+l-1} e^{-i2\pi f t \Delta t} \right|^{2}, \quad l = 1 \ (n) \ N - N_{S} + 1,$$



Analysis of HRV Data via WOSA



where h_1, \ldots, h_{N_S} is a data taper.

• Then the WOSA spectral estimator is defined by

$$\widehat{S}^{(WOSA)}(f) = \frac{1}{N_B} \sum_{j=0}^{N_B - 1} \widehat{S}^{(d)}_{jn+1}(f) .$$

A robust spectral estimator can be obtained by replacing the sample mean by an M-estimator (cf. Chave et al., 1987), i.e.,

 $\min_{\theta} \sum \rho\left(\frac{x_i - \theta}{s}\right) \text{ , or, equivalently, } \sum \psi\left(\frac{x_i - \theta}{s}\right) = 0 \text{ ,}$

where x_i corresponds to $\widehat{S}_{jn+1}^{(d)}(f)$ and $\psi(r) = \rho'(r)$. The solution $\widehat{\theta}$ is called M-estimate. Because outlier contamination can only result in a spectrum that is biased upwards, a special asymmetric ρ -function is used. It is defined by

 $\psi(r) = r \exp(-\exp(\beta(r-\beta))) .$

The solution is calculated using iteratively reweighted least squares (IWLS) with proper initial values, e.g., the sample median and a corrected version of the median absolute deviation (MAD).



Summary & Discussion

• Simulated process

– spectral estimate using the robust filter-cleaner approach:	good
- robust WOSA spectral estimate:	poor

\bullet Analysis of HRV data

– spectral estimate using the robust filter-cleaner approach:	good
- robust WOSA spectral estimate:	good

References

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