

Problem 1

a) w.s. $\mu_t = \mu$
 $f(t_1, t_2) = r(t_2 - t_1)$

invertible if a process can be represented by a finite or infinite AR-process.

$$z_t - \phi_2 z_{t-2} = a_t$$

Characteristic equation $x^2 - \phi_2 = 0 \Rightarrow x = \pm \sqrt{\phi_2}$

The roots are less than one in absolute value for $|\phi_2| < 1$ and the process is stationary for $|\phi_2| < 1$

$\{z_t\}$ is always invertible.

b). We have $z_{t+1} = \phi_2 z_{t-1} + a_{t+1}$

$$z_{t+2} = \phi_2 z_t + a_{t+2}$$

$$z_{t+3} = \phi_2 z_{t+1} + a_{t+3}$$

$$= \phi_2 (\phi_2 z_{t-1} + a_{t+1}) + a_{t+3}$$

$$= \phi_2^2 z_{t-1} + \phi_2 a_{t+1} + a_{t+3}$$

$$z_{t+4} = \phi_2 z_{t+2} + a_{t+4}$$

$$= \phi_2 (\phi_2 z_t + a_{t+2}) + a_{t+4} = \phi_2^2 z_t + \phi_2 a_{t+2} + a_{t+4}$$

Wir get.

$$Z_t(1) = \phi_2 Z_{t-1},$$

$$e_t(1) = a_{t+1}$$

$$Z_t(2) = \phi_2 Z_t,$$

$$e_t(2) = a_{t+2}$$

$$Z_t(3) = \phi_2^2 Z_{t-1},$$

$$e_t(3) = \phi_2 a_{t+1} + a_{t+3}$$

$$Z_t(4) = \phi_2^2 Z_t,$$

$$e_t(4) = \phi_2 a_{t+2} + a_{t+4}$$

Problem 2.

$$Z_t = \sum_{j=0}^{\infty} \psi_j a_{t-j}$$

$$\sum_{j=0}^{\infty} |\psi_j| < \infty$$

$$\gamma(k) = E \left[\sum_{j=0}^{\infty} \psi_j a_{t-j} \sum_{s=0}^{\infty} \psi_s a_{t-k-s} \right]$$

$$= \sum_{j=0}^{\infty} \sum_{s=0}^{\infty} \psi_j \psi_s E(a_{t-j} a_{t-k-s})$$

$$= \frac{\sigma_a^2}{\sigma_a^2} \sum_{j=0}^{\infty} \psi_j \psi_{j-k}$$

a)

$$Z_t - \phi Z_{t-1} = a_t + \theta a_{t-1}, \quad |\phi| < 1, \quad |\theta| < 1$$

$$Z_t = (1 - \phi B)^{-1} (1 + \theta B) a_t = \psi(B) a_t$$

$$(1 + \theta B) = (1 - \phi B) (\psi_0 + \psi_1 B + \psi_2 B^2 + \psi_3 B^3 + \dots)$$

$$\psi_0 = 1$$

$$\psi_1 - \psi_0 \phi = \theta \quad \Rightarrow \quad \psi_1 = \phi + \theta$$

$$\psi_2 - \phi \psi_1 = 0 \quad \Rightarrow \quad \psi_2 = \phi(\phi + \theta)$$

$$\psi_3 - \phi \psi_2 = 0 \quad \Rightarrow \quad \psi_3 = \phi^2(\phi + \theta)$$

$$\psi_k = \phi^{k-1} (\phi + \theta)$$

We get:

$$\begin{aligned} \sigma(0) &= \sigma^2 \sum_{j=0}^{\infty} \psi_j^2 = \sigma^2 (1 + (\phi+\theta)^2 + \phi^2(\phi+\theta)^2 + \phi^4(\phi+\theta)^2 + \dots) \\ &= \sigma^2 \left(1 + \frac{(\phi+\theta)^2}{1-\phi^2} \right) = \frac{\sigma^2 (1 + 2\phi\theta + \theta^2)}{1-\phi^2} \end{aligned}$$

$$\begin{aligned} \sigma(1) &= \sigma^2 \sum_{j=0}^{\infty} \psi_j \psi_{j-1} = \sigma^2 (\psi_1 + \psi_2 \psi_1 + \psi_3 \psi_2 + \psi_4 \psi_3 + \dots) \\ &= \sigma^2 ((\phi+\theta) + \phi(\phi+\theta)^2 + \phi^3(\phi+\theta)^2 + \phi^5(\phi+\theta)^2 + \dots) \\ &= \sigma^2 (\phi+\theta) (1 + \phi(\phi+\theta) + \phi^3(\phi+\theta) + \phi^5(\phi+\theta) + \dots) \\ &= \sigma^2 (\phi+\theta) \left(1 + \frac{\phi(\phi+\theta)}{1-\phi^2} \right) = \frac{\sigma^2 (\phi+\theta) (1 - \phi^2 + \phi^2 + \theta\phi)}{1-\phi^2} \\ &= \frac{2\sigma^2 (\phi+\theta) (1 + \theta\phi)}{1-\phi^2} \end{aligned}$$

Problem 3

a)

$$z_t = \phi_1 z_{t-1} + \phi_2 z_{t-2} + a_t$$

\Rightarrow

$$z_{t+1} = \phi_1 z_t + \phi_2 z_{t-1} + a_{t+1}$$

$$z_{t+2|t+1} = \phi_1 z_{t+1} + \phi_2 z_t$$

$$= \phi_1 z_{t+1|t} + \phi_2 z_t + \phi_1 a_{t+1}$$

which gives

$$\begin{bmatrix} z_{t+1|t+1} \\ z_{t+2|t+1} \end{bmatrix} = \begin{bmatrix} 0 & 1 \\ \phi_2 & \phi_1 \end{bmatrix} \begin{bmatrix} z_{t|t} \\ z_{t+1|t} \end{bmatrix} + \begin{bmatrix} 1 \\ \phi_1 \end{bmatrix} a_{t+1}$$

$$z_t = y_t = \begin{bmatrix} 1 & 0 \end{bmatrix} \begin{bmatrix} z_{t|t} \\ z_{t+1|t} \end{bmatrix}$$

$$z_t = \phi z_{t-1} + a_t + \theta a_{t-1}$$

$$z_{t+1} = \phi z_t + \theta a_t + a_{t+1}$$

$$\begin{aligned} z_{t+2|t+1} &= \phi z_{t+1} + \theta a_{t+1} \\ &= \phi(\phi z_t + \theta a_t) + \phi a_{t+1} + \theta a_{t+1} \\ &= \phi(z_{t+1|t}) + (\phi + \theta)a_{t+1} \end{aligned}$$

$$\begin{bmatrix} z_{t+1|t+1} \\ z_{t+2|t+1} \end{bmatrix} = \begin{bmatrix} 0 & 1 \\ 0 & \phi \end{bmatrix} \begin{bmatrix} z_{t+1|t} \\ z_{t+1|t} \end{bmatrix} + \begin{bmatrix} 1 \\ \phi + \theta \end{bmatrix} a_{t+1}$$

$$y_t = [1, \theta] \begin{bmatrix} z_{t|t} \\ z_{t+1|t} \end{bmatrix}$$

b)

Generation of forecasts.

Estimation of signal when the time series is observed with noise.

c)

$$X_t = F X_{t-1} + V_t \quad \text{Cov}(V_t) = Q$$

$$y_t = G X_t + W_t \quad \text{Cov}(W_t) = R$$

Define

$$\mu_{s|t} = E[X_s | y_t, y_{t-1}, \dots]$$

$$\Omega_{s|t} = \text{Cov}[X_s | y_t, y_{t-1}, \dots]$$

$$\mu_{t+k|t} = E[F X_{t+k-1|t} + V_{t+k} | y_t, y_{t-1}, \dots]$$

$$= F \mu_{t+k-1|t}$$

$$\Omega_{t+k|t} = \text{Cov}[F X_{t+k-1|t} + V_{t+k} | y_t, y_{t-1}, \dots]$$

$$= F \Omega_{t+k-1|t} F' + Q.$$

d)

$$F = \begin{bmatrix} 0 & 1 \\ \phi_2 & \phi_1 \end{bmatrix} =$$

$$|F - \lambda I| = \begin{vmatrix} -\lambda & 1 \\ \phi_2 & \phi_1 - \lambda \end{vmatrix} = 0$$

$$\Rightarrow -\phi_1 \lambda + \lambda^2 - \phi_2 = 0$$

$$\text{or } \lambda^2 - \phi_1 \lambda - \phi_2 = 0,$$

$|\lambda| < 1 \Leftrightarrow$ AR(2) process is weakly stationary