EE402 - Discrete Time Systems **Spring 2018**

Lecture 3

Lecturer: Asst. Prof. M. Mert Ankarali

Difference Equations

In discrete-time domain, we have difference equations that replaces differential equations. We are mainly interested in LTI systems, that are represented by linear constant coefficient difference equations. Let $x[k]$ and $y[k]$ be the input and output respectively, then an LTI difference equation can be expressed as

$$a_0 y[k] + a_1 y[k-1] + ... + a_N y[k-N] = b_0 x[k] + ... + b_M x[k-M]$$
$$\sum_{n=1}^{N} a_n y[k-n] = \sum_{n=1}^{M} b_n x[k-n]$$

Unlike ODEs difference equations are very easy to solve computationally or simulate in computer environment. Let's consider the following first-order difference equation

$$y[k] = \frac{1}{2} y[k-1] + x[k] \quad , x[k] = 0 \ \& \ y[k] = 0, \ \text{for} k < 0$$

Let's "simulate" the difference equation for $x[k] = \delta[k]$.

$$\begin{aligned} y[0] &= \frac{1}{2} y[-1] + x[0] = 0 + 1 = 1 \\ y[1] &= \frac{1}{2} y[0] + x[1] = \frac{1}{2} + 0 = \frac{1}{2} \\ y[2] &= \frac{1}{2}\frac{1}{2} = \frac{1}{4} \\ y[3] &= \frac{1}{2}\frac{1}{4} = \frac{1}{8} \\ &\vdots \\ y[k] &= \left(\frac{1}{2}\right)^k \end{aligned}$$

Now let's simulate for $x[k] = u[k]$

$$\begin{aligned} y[0] &= 0 + 1 = 1 \\ y[1] &= \frac{1}{2} + 1 \\ y[2] &= \frac{1}{4} + \frac{1}{2} + 1 \\ y[3] &= \frac{1}{8} + \frac{1}{4} + \frac{1}{2} + 1 \\ &\vdots \\ y[k] &= \frac{1}{2^k} + \cdots + \frac{1}{2} + 1 = 2 - \left(\frac{1}{2}\right)^k \end{aligned}$$

This is a great method for "simulating" using a computational approach, but in general it may be very hard to get a closed from expression. The most basic solution method is solving the difference equation directly in time domain by trying to find a "basis" for the solution space similar to the operation in ODEs. We try sequences/signals of the form λ^k , $k > 0$ to find a solution form for the homogeneous equation. Let's apply this method for the first-order difference equation above

$$\begin{aligned} y[k] = \lambda^k \ \rightarrow y[k] - \frac{1}{2}y[k-1] &= 0 \\ \lambda^k - \frac{\lambda^{k-1}}{2} &= 0 \\ \lambda^{k-1}\left(\lambda - \frac{1}{2}\right) &= 0 \\ \lambda - \frac{1}{2} &= 0 \end{aligned}$$

Where the last equation is the characteristic equation of the difference equation. Since the characteristic equation has one root only, we obtain a solution of the form

$$y[k] = y_h[k] + y_p[k] = C\left(\frac{1}{2}\right)^k + y_p[k]$$

Let's assume that for $x[k] = u[k]$ particular solution has the form $y_p[k] = A$ for $k > 0$ then

$$A = \frac{1}{2}A + 1 \ \rightarrow A = 2$$

Now let's find C using the fact that $y[k] = 0$ for $k < 0$

$$y[0] = \frac{1}{2}y[-1] + x[0] \ \rightarrow \ y[0] = 1$$

$$1 = C\left(\frac{1}{2}\right)^0 + 2 \rightarrow C = -1$$

Then the solution can be written as

$$y[k] = -\left(\frac{1}{2}\right)^k + 2$$

Example 1.1 Find the general form of the homogeneous solution for the following difference equation

$$y[k] - 3y[k-1] + 2y[k-2] = x[k]$$

Solution:

$$\begin{aligned} &\lambda^2 - 3\lambda + 2 = 0 \\ &\lambda_1 = 1 \ \& \ \lambda_2 = 2 \\ &y[k] = C_1 + C_2 2^k \ , k > 0 \end{aligned}$$

Example 1.2 Now let's assume that $y[k] = 0$ for $k < 0$ and $x[k] = 3^k$, then find $y[k]$ for $k \geq 0$.

Solution: First let's find a particular solution. Let's assume that $y_p[k] = A3^k$, then

$$A3^k - 3A3^{k-1} + 2A3^{k-2} = 3^k \ \rightarrow \ A = 9/2$$

$$y_p[k] = 4.5 \ 3^k$$

Now let's try to find C_1 and C_2

$$
\begin{aligned}
&y[k] - 3y[k-1] + 2y[k-2] = x[k] \\
&y[0] = x[0] \ \rightarrow \ C_1 + C_2 = -3.5 \\
&y[1] - 3y[0] = x[1] \ \rightarrow \ C_1 + C_2 2 = -7.5 \\
&C_1 = 0.5 \ \& \ C_2 = -4 \\
&y[k] = 0.5 - 4\,2^k + 4.5\,3^k \ , k > 0
\end{aligned}
$$

What about repeated roots? Possible mini project question

Example 2 Find the general form of the homogeneous solution for the following difference equation

$$y[k] + 4y[k-2] = x[k]$$

Solution:

$$
\begin{aligned}
&\lambda^2 + 4 = 0 \ \rightarrow \ \lambda_{1,2} = \pm 2j \\
&y[k] = C_1(2j)^k + C_2(-2j)^k = C_1 2^k e^{jk\pi/2} + C_2 2^k e^{-jk\pi/2} \\
&y[k] = \bar{C}_1 2^k \frac{e^{jk\pi/2} + e^{-jk\pi/2}}{2} + \bar{C}_2 2^k \frac{e^{jk\pi/2} - e^{jk\pi/2}}{2j} \\
&y[k] = \bar{C}_1 2^k \cos(k\pi/2) + \bar{C}_2 2^k \sin(k\pi/2)
\end{aligned}
$$

How we can generalize this to arbitrary complex conjugate roots? Possible mini project question

What is the home message? Similar to ODEs time domain solution of difference equations is generally "messy".

Z-transform & Difference Equations

Difference Equations to Z-transform

Let's consider the following difference equation with $y[n]$ and $x[n]$ be the strictly causal input–output pair.

$$a_0 y[k] + a_1 y[k-1] + ... + a_N y[k-N] = b_0 x[k] + ... + b_M x[k-M]$$

Now let's assume that $\mathcal{Z}\{x[k]\} = X(z)$ and $\mathcal{Z}\{y[k]\} = Y(z)$. If we take the Z-transform fo the both sides of the equation by applying the shifting theorem we obtain

$$
\begin{aligned}
a_0 Y(z) + a_1 z^{-1} Y(z) + ... + a_N z^{-N} Y(z) &= b_0 X(z) + ... + b_M z^{-M} X(z) \\
(a_0 + a_1 z^{-1} + ... + a_N z^{-N}) Y(z) &= (b_0 + b_1 z^{-1} + ... + b_M z^{-M}) X(z) \\
\frac{Y(z)}{X(z)} = G(z) &= \frac{b_0 + b_1 z^{-1} + ... + b_M z^{-M}}{a_0 + a_1 z^{-1} + ... + a_N z^{-N}} \\
&= z^{N-M} \frac{b_0 z^M + b_1 z^{M-1} + ... + b_M}{a_0 z^N + a_1 z^{N-1} + ... + a_N}
\end{aligned}
$$

Under "zero initial conditions" if we can find $X(z)$, then we can compute $Y(z)$ using $Y(z) = G(z)X(z)$. After that we can take the inverse z-transform and compute $y[k]$.

Example 3.1 Compute $y[k]$ using the Z-transform method

$$y[k] = \frac{1}{2}y[k-1] + x[k]$$
$$y[k] = 0,\ \text{for } k < 0 \ \&\ x[k] = \delta[k]$$

Solution:

$$Y(z) = \frac{1}{2}Y(z)z^{-1} + X(z) \ \rightarrow\ \frac{Y(z)}{X(z)} = G(z) = \frac{z}{z-1/2}$$
$$Y(z) = \frac{z}{z-1/2} \ \rightarrow\ y[k] = \left(\frac{1}{2}\right)^k$$

Example 3.2 Now let's compute $y[k]$ for $x[k] = u[k]$

$$Y(z) = G(z)X(z) \ \rightarrow\ Y(z) = \frac{z^2}{(z-1/2)(z-1)}$$
$$Y(z) = -\frac{z}{z-1/2} + 2\frac{z}{z-1}$$
$$y[k] = 2 - \left(\frac{1}{2}\right)^k$$

Example 4 For the following difference equation, compute $y[k]$ for $x[k] = x[k] = 3^k u[k]$

$$y[k] - 3y[k-1] + 2y[k-2] = x[k]$$

Solution:

$$Y(z)(1 - 3z^{-1} + 2z^{-2}) = X(z) \ \rightarrow\ G(z) = \frac{z^2}{z^2 - 3z + 2} = \frac{z^2}{(z-1)(z-2)}$$
$$Y(z) = \frac{z^3}{(z-1)(z-2)(z-3)} = 0.5\frac{z}{z-1} - 4\frac{z}{z-2} + 4.5\frac{z}{z-3}$$
$$y[k] = \left(0.5 - 4\ 2^k + 4.5\ 3^k\right)u[k]$$

Z-transform to Difference Equations

Sometimes the Z-domain transfer function of a system is given, and we may be supposed to find the difference equation representation. Let's assume that we have a general transfer function that can be represented in terms of ratio of two polynomials in z or z^{-1} as given below

$$\frac{Y(z)}{X(z)} = G(z) = \frac{b_0 + b_1 z^{-1} + ... + b_M z^{-M}}{a_0 + a_1 z^{-1} + ... + a_N z^{-N}} = z^{N-M}\frac{b_0 z^M + b_1 z^{M-1} + ... + b_M}{a_0 z^N + a_1 z^{N-1} + ... + a_N}$$

In his case, I prefer to work with the polynomials that are written in terms of z^{-1}. Let's manipulate the Z-domain equation to obtain

$$Y(z)(a_0 + a_1 z^{-1} + ... + a_N z^{-N}) = X(z)(b_0 + b_1 z^{-1} + ... + b_M z^{-M})$$
$$a_0 Y(z) + a_1 z^{-1} Y(z) + ... + a_N z^{-N} Y(z) = b_0 X(z) + b_1 z^{-1} X(z) + ... + b_M z^{-M} X(z)$$

Let's assume that $\mathcal{Z}^{-1}\{Y(z)\} = y[k]$ and $\mathcal{Z}^{-1}\{X(z)\} = x[k]$. If we take the inverse Z-transform of both sides by applying the shifting theorem we obtain

$$a_0 y[k] + a_1 y[k-1] + ... + a_N z^{-N} y[k-N] = b_0 x[k] + b_1 x[k-1] + ... + b_M x[k-M]$$

We can use this conversion to "simulate" a given discrete time transfer function or realizing the given system (it may be a filter or controller) to implement on an embedded platform.

It can also be used for computationally finding the inverse Z-transform of a given z-domain rational function. The next example will illustrate this feature.

Example 5 Find a computational solution for the inverse Z-transform of $H(z) = \frac{z^{-1}}{1-2z^{-1}+z^{-2}}$ by using the conversion from Z-domain transfer function to difference equation concept.

Solution: Let's assume that $H(z)$ is a "transfer function" not an arbitrary z-domain function. Then $\mathcal{Z}^{-1}\{H(z)\} = h(t)$ becomes the impulse response of the "system". Thus we can assume some imaginary input-output pair $y[n]$ and $x[n]$ where

$$\frac{Y(z)}{X(z)} = H(z)$$

If we can find a difference equation realization for $H(z)$ then we can simulate the difference equation by assuming $x[k] = \delta[k]$ (i.e. unit impulse input). So let's find a realization for the given $H(z)$ as

$$\begin{aligned} \frac{Y(z)}{X(z)} &= \frac{z^{-1}}{1-2z^{-1}+z^{-2}} \\ Y(z) - 2z^{-1}Y(z) + z^{-2}Y(z) &= z^{-1}X(z) \\ y[k] - 2y[k-1] + y[k-2] &= x[k-1] \end{aligned}$$

Now let's simulate the above equation for $x[k] = \delta[k]$

$$\begin{aligned} y[k] &= 2y[k-1] - y[k-2] + x[k-1] \\ y[0] &= 2y[-1] - y[-2] + x[-1] = 0 \\ y[1] &= 2y[0] - y[-1] + x[0] = 1 \\ y[2] &= 2y[1] - y[0] + x[1] = 2 \\ y[3] &= 2y[2] - y[1] + x[2] = 3 \\ y[4] &= 4 \\ &\cdots \\ y[k] &= k \end{aligned}$$