Fiche Mathematiques du Signal

Th. dw retard
$$Z[J(t-KT)] = JKF(3)$$

$$Z^{-1}[F(3)] = \{J(nT)\}$$

$$Sin(\omega f) = \frac{e^{i\omega} - e^{-i\omega}}{2i}$$

$$Cos(\omega f) = \frac{e^{i\omega} - e^{-i\omega}}{2}$$

F(p) =
$$\int f(1)e^{-pt}dt$$
 over $p \in C$

$$= \int hospite \int \int f(1)e^{-pt}dt + hug(1) = \lambda F(p) + \mu G$$

- Linearité
$$\lambda \left[\lambda f(f) + \mu g(f) \right] = \lambda F(p) + \mu G(p)$$
- retard $\lambda \left[f(f-Z) \right] = e^{-zp} F(p)$

- Dérivation
$$\angle \left[\frac{df(f)}{dt}\right] = pf(p) - f(t=0)$$

- Convolution $\angle \left[\frac{df(f)}{dt}\right] = F(p)G(p)$

$$\lim_{t\to\infty} f(t) = \lim_{t\to\infty} f(t)$$

ble simple

F(S) =
$$\sum_{Poles p:} Residus de \frac{F(P)}{1-e^{-T}P^{-1}}$$