Discrete Lowpass Filters

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Introduction

Digital (finite-difference) implementation first and second-order lowpass filters for use in control.

1 First-Order Lowpass

1.1 Analog Form

We can write the transfer function for a first-order lowpwass filter as

$$H(s) = \frac{Y(s)}{X(s)} = \frac{1}{(\tau)s + 1} = \frac{\omega_c}{s + \omega_c}$$

where τ is the time constant in seconds and ω_c is the cut-off freuency in rad/s.

1.2 Discrete Euler Implementation

The discrete approximation of this filter is often written as

$$y[k] = (1 - \alpha)y[k-1] + (\alpha)x[k]$$

where the smoothing factor $0 \leq \alpha \leq 1$ is

$$\begin{aligned} \alpha &= \frac{\Delta t}{\tau + \Delta t} = \frac{1}{1 + (\tau/\Delta t)} \\ &= \frac{\omega_c(\Delta t)}{(\omega_c(\Delta t) + 1)}. \end{aligned}$$

`https://en.wikipedia.org/wiki/Low-pass_filter#Discrete-time_realization` `http://techteach.no/simview/lowpass_filter/doc/filter_algorithm.pdf`

Working backwards we can define the transfer function for this as

$$H(z) = \frac{\alpha}{1 + (1 - \alpha)z^{-1}}$$

1.3 Bilinear Transform

An alternate form is derived is we apply the bilinear transform to the original transfer function. Write the transfer function in normalized form

$$H(s) = \frac{1}{\left(\frac{s}{\omega_{ac}}\right) + 1}$$

Apply a pre-warping transformation to calculate the equivalent analog cut-off frequency

$$\omega_{ac} = \tan\left(\frac{\omega_c(\Delta t)}{2}\right)$$

and let

$$c = \frac{1}{\omega_{ac}} = \cot\left(\frac{\omega_c(\Delta t)}{2}\right)$$

Substitute

$$H(s) = \frac{1}{(c)s + 1}$$

Apply bilinear transform using $s = (1 - z^{-1})/(1 + z^{-1})$

$$H(z) = \frac{1}{c\left(\frac{1-z^{-1}}{1+z^{-1}}\right) + 1}$$

$$H(z) = \frac{1 + z^{-1}}{(1 + c) + (1 - c)z^{-1}}$$

then covert to a difference equation

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

which agrees wtih the coefficients listed at `http://www.apicsllc.com/apics/Sr_3/Sr_3.htm`.

`https://ocw.mit.edu/courses/mechanical-engineering/2-161-signal-processing-continuous` `lecture-notes/lecture_19.pdf`

2 Second-Order Butterworth Filter

2.1 Analog Form

We can write the transfer function for the normalized frequency $a = \frac{s}{\omega_c}$ where ω_c is the cut-off frequency in rad/s as

$$H(a) = \frac{1}{a^2 + (\sqrt{2})a + 1}.$$

This can then be written in terms of the of ω_c as

$$H(s) = \frac{\omega_c^2}{s^2 + (\sqrt{2})\omega_c s + \omega^2}$$

The frequency response of this analog transfer function is shown in Figure 1

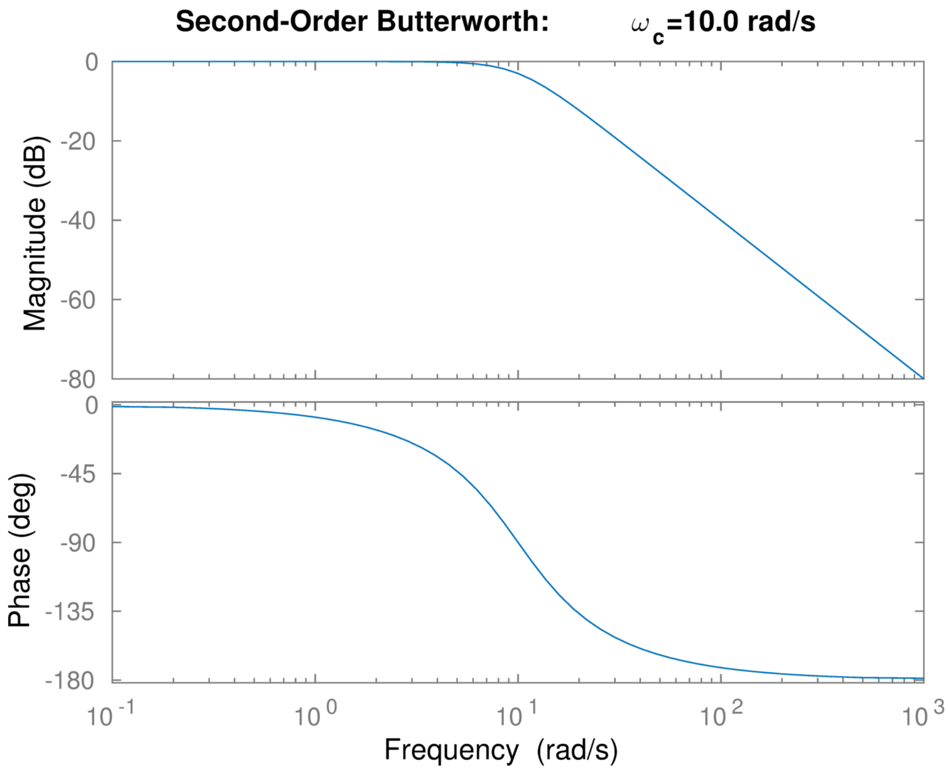

Figure 1: Analog frequency response.

3 Digital Form

The general second-order IIR filter can be expressed as

$$H(z) = \frac{n_0 + n_1 z^{-1} + n_2 z^{-2}}{d_0 + d_1 z^{-1} + d_2 z^{-2}}.$$

The resulting difference equation, assuming $x[k]$ as input and $y[k]$ as output is

$$y[k] = \frac{1}{d_0}\left[-d_1(y[k-1]) - d_2(y[k-2]) + n_0(x[k]) + n_1(x[k-1]) + n_2(x[k-2])\right]$$

For the Butterworth low-pass filter the coefficicients are

$$\begin{aligned} n_0 &= 1 \\ n_1 &= 2 \\ n_2 &= 1 \\ d_0 &= c^2 + (\sqrt{2})c + 1 \\ d_1 &= -2(c^2 - 1) \\ d_2 &= c^2 - (\sqrt{2})c + 1 \end{aligned}$$

where

$$c = \cot\left(\frac{\omega_c(\Delta t)}{2}\right)$$

is the inverse of the pre-warped equivalent cut-off frequency[1]

$$\omega_{ac} = \tan\left(\frac{\omega_c(\Delta t)}{2}\right)$$

and Δt is the sample time in seconds. See `http://www.apicsllc.com/apics/Sr_3/Sr_3.htm`.

Making the substitution we arrive at

$$y[k] = \frac{1}{(c^2 + (\sqrt{2})c + 1)}\Big[2(c^2 - 1)(y[k-1]) - (c^2 - (\sqrt{2})c + 1)(y[k-2]) \\ + x[k] + 2(x[k-1]) + x[k-2]\Big]$$

3.1 Derivation of General Second Order Butterworth Filter

Start with the general analog Butterworth transfer function.

$$H(s) = \frac{\omega_c^2}{s^2 + (\sqrt{2})\omega_c s + \omega^2}$$

Put into normalized from

$$H(s) = \frac{1}{\left(\frac{s}{\omega_{ac}}\right)^2 + (\sqrt{2})\left(\frac{s}{\omega_{ac}}\right) + 1}$$

where ω_{ac} is the equivalent analog cut-off frequency after pre-warping. Apply the warping function

$$\omega_{ac} = \tan\left(\frac{\omega_c(\Delta t)}{2}\right)$$

and let

$$c = \frac{1}{\omega_{ac}} = \cot\left(\frac{\omega_c(\Delta t)}{2}\right)$$

Substitute c into the transfer function

$$H(s) = \frac{1}{(cs)^2 + (\sqrt{2})(cs) + 1}$$

Now perform the bilinear transform by substituting

$$s = \frac{z-1}{z+1} = \frac{1 - z^{-1}}{1 + z^{-1}}$$

to get

$$H(z) = \frac{(1 + z^{-1})^2}{c^2(1 - z^{-1})^2 + (\sqrt{2})c(1 - z^{-1})(1 + z^{-1}) + (1 + z^{-1})^2}$$

$$H(z) = \frac{1 + 2z^{-1} + z^{-2}}{(c^2 + (\sqrt{2})c + 1) - 2(c^2 - 1)z^{-1} + (c^2 - (\sqrt{2})c + 1)z^{-2}}$$

[1] `https://www.staff.ncl.ac.uk/oliver.hinton/eee305/Chapter5.pdf`

4 Verification and Comparison

Figure 2 illustrates the frequency reponse of the three digital filters. The frequency response is determined from the z-domain transfer funtions. for the two first-order implementations We can see that the simpler alpha-filter implementation has an equivalent frequency response to the bilinear implementation.

For the second-order Butterworth filter, the frequncy reponse verifies that the bilinear transform, with pre-warping the critical frequency, reproduces the analog frequency response of the design.

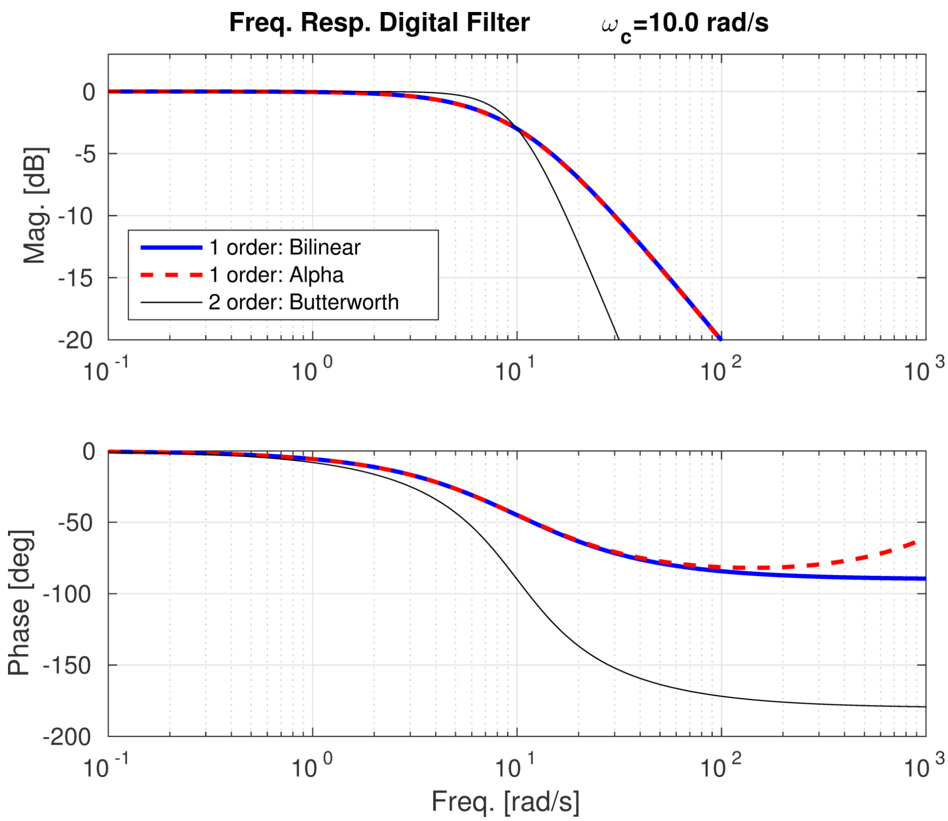

Figure 2: Frequency response of digital implementation.