

1. The Continuous Solution

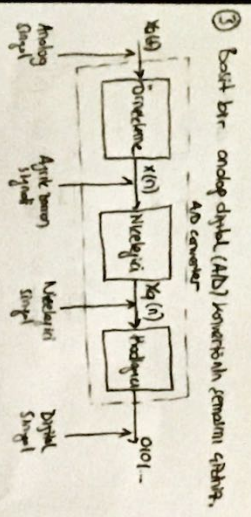
1) Verilen sürekli girici $x(t)$, kompleks değerli $x_2(t)$, gerç. kanalla $y(t)$ ve çık. sinyal $I(t; y(t))$ olup olamayacağı belirleniyor.

$$x_1(t) = A \sin 3\pi t$$

$$x_2(t) = A e^{j3\pi t} = A \cos 3\pi t + j A \sin 3\pi t$$

$$y(t) = \begin{bmatrix} x_1(t) \\ x_2(t) \end{bmatrix}$$

$$I(t; y(t)) = \begin{bmatrix} I_1(y_1(t)) \\ I_2(y_2(t)) \end{bmatrix}$$



2) 1.4.1'e göre sürekli sinyal dönüşümü

$$x_1(t) = \cos 2\pi (10) t$$

$$x_2(t) = \cos 2\pi (100) t$$

$$F_s = 400 \text{ Hz}$$

$$x_1(n) = \cos 2\pi \left(\frac{10}{400}\right) n = \cos \frac{\pi}{20} n$$

$$x_2(n) = \cos 2\pi \left(\frac{100}{400}\right) n = \cos \frac{\pi}{4} n = \cos \left(2\pi + \frac{\pi}{4}\right) = \cos \frac{\pi}{4} n$$

3) Örnekleme 1.4.2'ye göre sürekli sinyal dönüşümü.

$$x_1(t) = 3 \cos 100\pi t$$

- a) Sampling rate?
- b) $F_s = 200 \text{ Hz}$ ise $y(n) = ?$
- c) $F_s = 75 \text{ Hz}$ ise $x(n) = ?$
- d) Çıkış sinyali için analog sinyalin frekansı.

$$F_s = 200 \text{ Hz}$$

$$F_s = 2F = 2 \cdot 100 = 200 \text{ Hz}$$

$$y(n) = 3 \cos \left(\frac{100\pi}{200}\right) n = 3 \cos \frac{\pi}{2} n$$

$$c) x(n) = 3 \cos \left(\frac{100\pi}{75}\right) n = 3 \cos \frac{4\pi}{3} n = 3 \cos \left(2\pi - \frac{2\pi}{3}\right) = 3 \cos \frac{2\pi}{3}$$

$$d) F = 75 \text{ Hz}$$

$$F = \frac{1}{T} \text{ ise } T = \frac{1}{75} \text{ s}$$

$$y_1(t) = 3 \cos 2\pi F t = 3 \cos 2 \cdot 15\pi t = 3 \cos 30\pi t$$

5) Tonal discrete-time signalın not. ifadesi girilecek şekilde.

Unit sample, unit step, unit ramp, exponential signal

$$\delta(n) = \begin{cases} 1, & n=0 \\ 0, & n \neq 0 \end{cases}$$

Unit step

$$u(n) = \begin{cases} 1, & n \geq 0 \\ 0, & n < 0 \end{cases}$$

Unit ramp

$$r(n) = \begin{cases} n, & n \geq 0 \\ 0, & n < 0 \end{cases}$$

Exponential signal

$$x(n) = a^n$$

$$x(n) = r^n \quad (\cos n + j \sin n)$$

$$|x(n)| = A(n) = r^n$$

$$\angle x(n) = \phi(n) = \theta n$$

$$x(n) = \delta(n)$$

$$x(n) = \cos n$$

$$x(n) = \sin n$$

$$x(n) = e^{jn}$$

$$x(n) = \cos n$$

6) Örnekleme 2.2.4'e göre sürekli sinyal dönüşümü

$$x(n) = \sum_{k=-\infty}^{\infty} \delta(n - k)$$

$$x(n) = \begin{cases} 1, & n=0 \\ 0, & \text{diğer} \end{cases}$$

$$x(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = x(n)$$

→ Çıkış, girişin yansımasıdır

$$y(n) = x(n-1)$$

$$x(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = x(n-1)$$

$$x(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

$$y(n) = \begin{cases} 1, & n=0 \\ 0, & n=1, 2, 3, \dots \end{cases}$$

7) A constant multiplier blok diagramını çiziniz.

$$y(n) = ax(n)$$

8) $y(n) = nx(n)$ lineer invariant blok diagramı çiziniz.

Başarı: 2.2.4

$$a) y(n) = x(n) - x(n-1)$$

$$b) y(n) = x(n-1) - x(n-2)$$

$$c) y(n) = x(n-1) - x(n-2)$$

$$d) y(n) = x(n-1)$$

$$e) y(n) = x(n)$$

$$f) y(n) = x(n-1)$$

$$g) y(n) = x(n-1)$$

$$h) y(n) = x(n-1)$$

$$i) y(n) = x(n-1)$$

$$j) y(n) = x(n-1)$$

$$k) y(n) = x(n-1)$$

$$l) y(n) = x(n-1)$$

$$m) y(n) = x(n-1)$$

$$n) y(n) = x(n-1)$$

$$o) y(n) = x(n-1)$$

9) $y(n) = Ax(n) + B$ lineer non-linear blok diagramı çiziniz.

Başarı: 2.2.5

$$a) y(n) = n x(n)$$

$$b) y(n) = x(n)^2$$

$$c) y(n) = x(n)^2$$

$$d) y(n) = Ax(n) + B$$

$$e) y(n) = e^{x(n)}$$

$$f) y(n) = x(n)$$

$$g) y(n) = x(n)$$

$$h) y(n) = x(n)$$

$$i) y(n) = x(n)$$

$$j) y(n) = x(n)$$

$$k) y(n) = x(n)$$

10) $y(n) = X(n) - X(n-1)$ causal non-causal blok diagramı çiziniz.

Başarı: 2.2.6

$$a) y(n) = x(n) - x(n-1)$$

$$b) y(n) = \sum_{k=-\infty}^n x(k)$$

$$c) y(n) = x(n)$$

$$d) y(n) = x(n) + 3x(n+1)$$

$$e) y(n) = x(n^2)$$

$$f) y(n) = x(2n)$$

$$g) y(n) = x(n)$$

$$h) y(n) = x(n)$$

$$i) y(n) = x(n)$$

$$j) y(n) = x(n)$$

$$k) y(n) = x(n)$$

$$l) y(n) = x(n)$$

$$m) y(n) = x(n)$$

$$n) y(n) = x(n)$$

$$o) y(n) = x(n)$$

$$p) y(n) = x(n)$$

$$q) y(n) = x(n)$$

$$r) y(n) = x(n)$$

$$s) y(n) = x(n)$$

$$t) y(n) = x(n)$$

$$u) y(n) = x(n)$$

$$v) y(n) = x(n)$$

$$w) y(n) = x(n)$$

$$x) y(n) = x(n)$$

$$y) y(n) = x(n)$$

$$z) y(n) = x(n)$$

$$aa) y(n) = x(n)$$

$$ab) y(n) = x(n)$$

$$ac) y(n) = x(n)$$

$$ad) y(n) = x(n)$$

11) LTI (Linear time invariant) sistemlerin birleştirilmesi

