

# Digital Signal Processing

## II. Discrete signals and systems

## II.1 Discrete signals

# Representation

A discrete signal can be represented:

- ▶ graphically
- ▶ in table form
- ▶ as a vector:  $x[n] = [\dots, 0, 0, 1, 3, 4, 5, 0, \dots]$ 
  - ▶ an **arrow** indicates the origin of time ( $n = 0$ ).
  - ▶ if the arrow is missing, the origin of time is at the first element
  - ▶ the dots ... indicate that the value remains the same from that point onwards

Examples: at blackboard

Notation:  $x[4]$  represents the value of the fourth sample in the signal  $x[n]$

# Basic signals

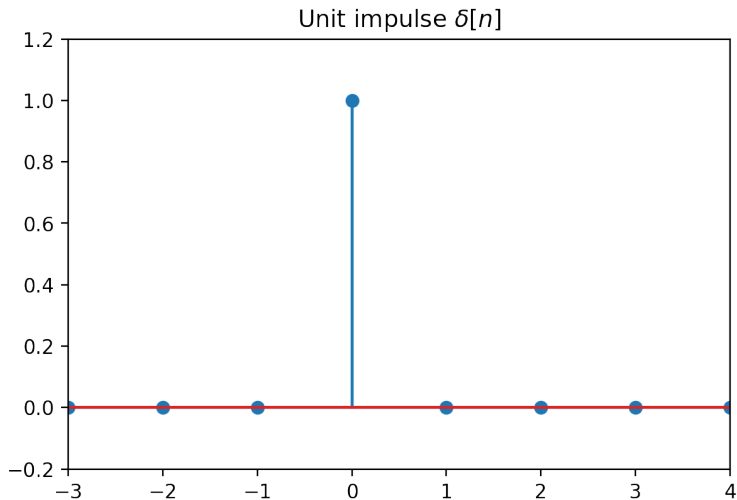
Some elementary signals are presented below.

## Unit impulse

Contains a single non-zero value of 1 located at time 0. It is denoted with  $\delta[n]$ .

$$\delta[n] = \begin{cases} 1 & \text{if } n = 0 \\ 0 & \text{otherwise} \end{cases}.$$

# Representation



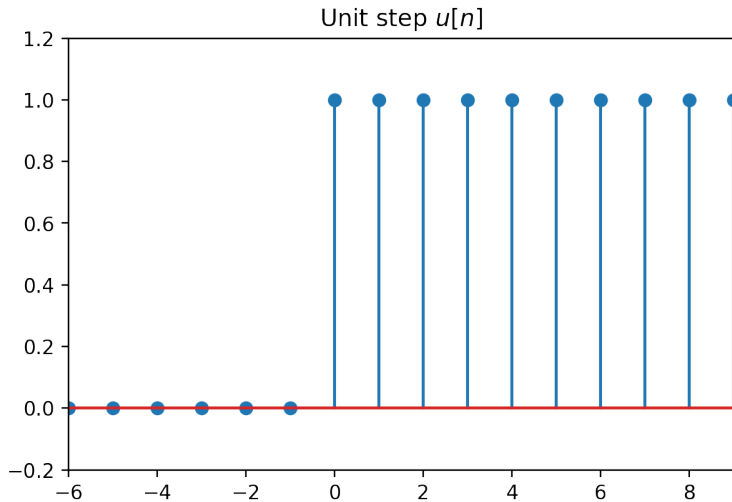
# Unit step

## Unit step

It is denoted with  $u[n]$ .

$$u[n] = \begin{cases} 1 & \text{if } n \geq 0 \\ 0 & \text{otherwise} \end{cases}.$$

# Representation





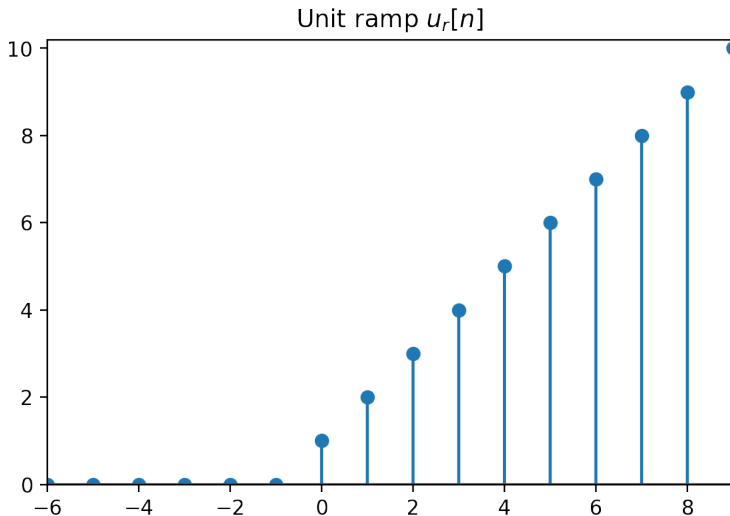
# Unit ramp

## Unit ramp

It is denoted with  $u_r[n]$ .

$$u_r[n] = \begin{cases} n & \text{if } n \geq 0 \\ 0 & \text{otherwise} \end{cases}.$$

# Representation



# Exponential signal

## Exponential signal

It does not have a special notation. It is defined by:

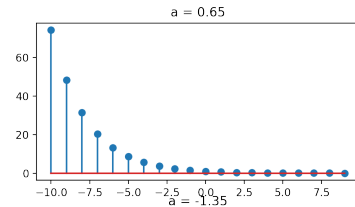
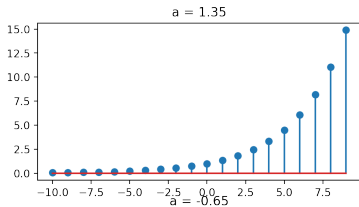
$$x[n] = a^n.$$

$a$  can be a real or a complex number. Here we consider only the case when  $a$  is real.

Depending on the value of  $a$ , we have four possible cases:

1.  $a \geq 1$
2.  $0 \leq a < 1$
3.  $-1 < a < 0$
4.  $a \leq -1$

# Representation



## II.2 Types of discrete signals

# Signals with finite energy

- ▶ The **energy of a discrete signal** is defined as

$$E = \sum_{n=-\infty}^{\infty} (x[n])^2.$$

- ▶ If  $E$  is finite, the signal is said to have finite energy.
- ▶ Examples:
  - ▶ unit impulse has finite energy
  - ▶ unit step does not

## Connection with DEDP class

- ▶ Cross-link with DEDP course:

$$E = \|\mathbf{x} - \mathbf{0}\|^2 = \|\mathbf{x}\|^2$$

- ▶ Energy of a signal = **squared Euclidean distance to 0**
  - ▶ geometric interpretation: squared length of the segment from 0 to the point  $\mathbf{x}$
  - ▶ holds for continuous signals as well:

$$E = \|\mathbf{x}\|^2 = \int_{-\infty}^{\infty} x^2(t) dt$$

# Signals with finite power

- ▶ The **average power of a discrete signal** is defined as

$$P = \lim_{N \rightarrow \infty} \frac{\sum_{n=-N}^N (x[n])^2}{2N + 1}.$$

- ▶ In other words, the average power is the average energy per sample.
- ▶ If  $P$  is finite, the signal is said to have finite power.
- ▶ A signal with finite energy has finite power ( $P = 0$  if the signal has infinite length). A signal with infinite energy can have finite or infinite power.
- ▶ Example: unit step has finite power  $P = \frac{1}{2}$  (proof at blackboard).



## Connection with DEDP class

- ▶ Average power = temporal average squared value  $\overline{X^2}$ 
  - ▶ i.e. average value of the square of samples

# Periodic and non-periodic signals

- ▶ A signal is called **periodic** if its values repeat themselves after a certain time (known as **period**).

$$x[n] = x[n + N], \forall t$$

- ▶ The **fundamental period** of a signal is the minimum value of  $N$ .
- ▶ Periodic signals have infinite energy, and finite power equal to the power of a single period.

## Even and odd signals

- ▶ A real signal is **even** if it satisfies the following symmetry:

$$x[n] = x[-n], \forall n.$$

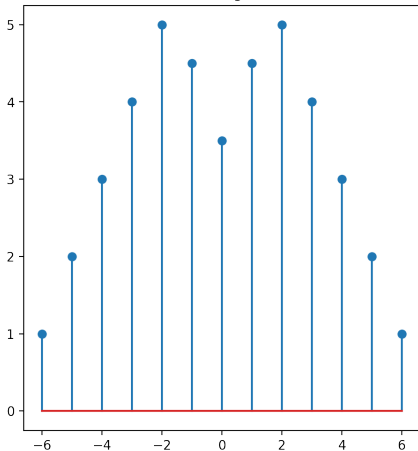
- ▶ A real signal is **odd** if it satisfies the following anti-symmetry:

$$-x[n] = x[-n], \forall n.$$

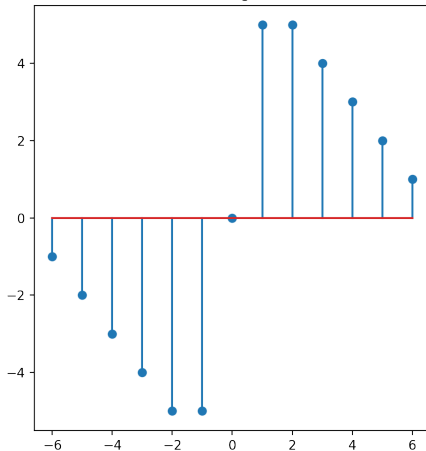
- ▶ There exist signals which are neither even nor odd.

# Even and odd signals: example

Even signal



Odd signal



## Even and odd parts of a signal

- ▶ Every signal can be written as the sum of an even signal and an odd signal:

$$x[n] = x_e[n] + x_o[n]$$

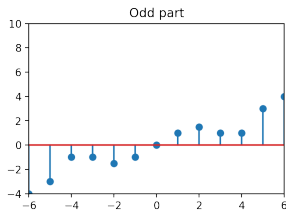
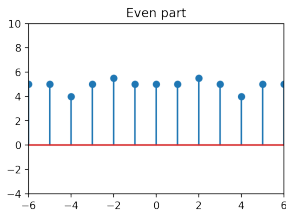
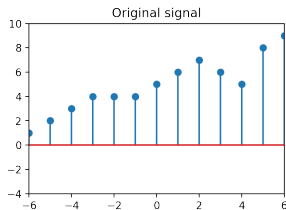
- ▶ The even and the odd parts of the signal can be found as follows:

$$x_e[n] = \frac{x[n] + x[-n]}{2}.$$

$$x_o[n] = \frac{x[n] - x[-n]}{2}.$$

- ▶ Proof: check that  $x_e[n]$  is even,  $x_o[n]$  is odd, and their sum is  $x[n]$

# Even and odd parts: example



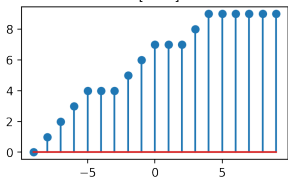
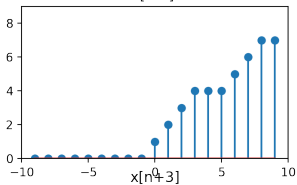
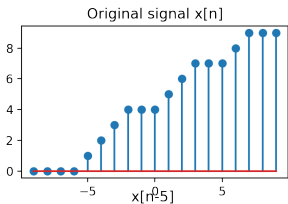
## II.3 Basic operations with discrete signals

# Time shifting

- ▶ The signal  $x[n - k]$  is  $x[n]$  **delayed with  $k$  time units**
  - ▶ Graphically,  $x[n - k]$  is shifted  $k$  units to the **right** compared to the original
- ▶ The signal  $x[n + k]$  is  $x[n]$  **anticipated with  $k$  time units**
  - ▶ Graphically,  $x[n + k]$  is shifted  $k$  units to the **left** compared to the original signal.

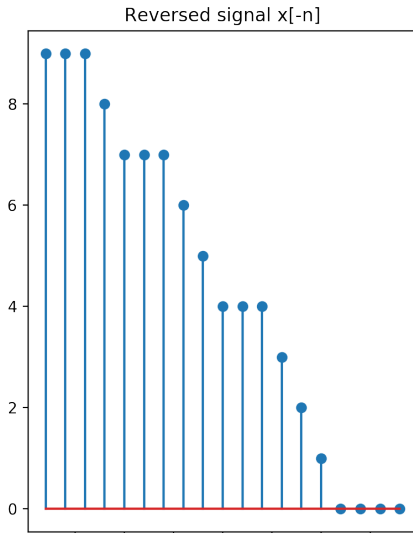
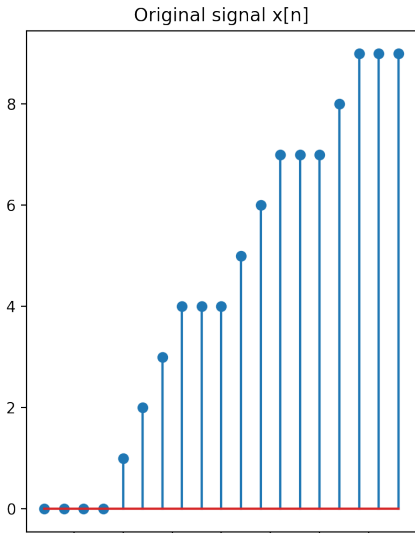


# Time shifting: representation



# Time reversal

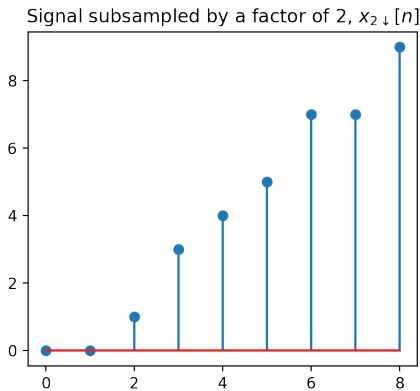
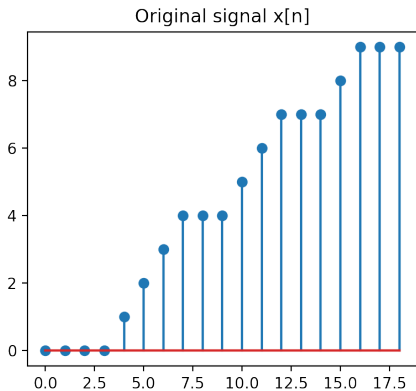
- ▶ Changing the variable  $n$  to  $-n$  produces a signal  $x[-n]$  which mirrors  $x[n]$ .



# Subsampling

- ▶ **Subsampling** by a factor of  $M$  = keep only 1 sample from every  $M$  of the original signal
  - ▶ Total number of samples is reduced  $M$  times

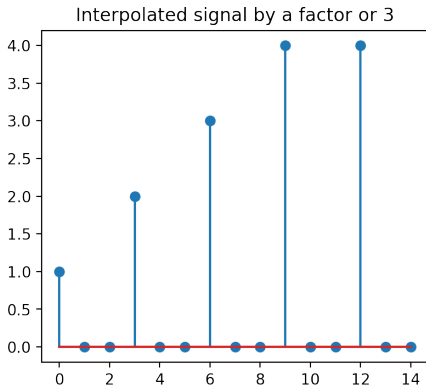
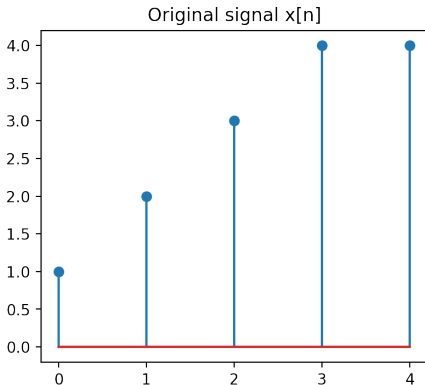
$$x_{M\downarrow}[n] = x[Mn]$$



# Interpolation

- **Interpolation** by a factor of  $L$  adds  $(L - 1)$  zeros between two samples in the original signal
  - Total number of samples increases  $L$  times

$$x_{L\uparrow} = \begin{cases} x[\frac{n}{L}] & \text{if } \frac{n}{L} \in \mathbb{N} \\ 0 & \text{otherwise} \end{cases}.$$



# Mathematical operations

- ▶ A signal  $x[n]$  can be **scaled** by a constant  $A$ , i.e. each sample is multiplied by  $A$ :

$$y[n] = Ax[n].$$

- ▶ Two signals  $x_1[n]$  and  $x_2[n]$  can be **summed** by summing the individual samples:

$$y[n] = x_1[n] + x_2[n]$$

- ▶ Two signals  $x_1[n]$  and  $x_2[n]$  can be **multiplied** by multiplying the individual samples:

$$y[n] = x_1[n] \cdot x_2[n]$$

## II.4 Discrete systems

# Definition

- ▶ **System** = a device or algorithm which produces an **output signal** based on an **input signal**
- ▶ We will only consider systems with a single input and a single output
- ▶ Figure here: blackboard.
- ▶ Common notation:
  - ▶  $x[n]$  is the input
  - ▶  $y[n]$  is the output
  - ▶  $H$  is the system.

# Notations

► Notations:

$$y[n] = H[x[n]]$$

(“the system  $H$  applied to the input  $x[n]$  produces the output  $y[n]$ ”)

$$x[n] \xrightarrow{H} y[n]$$

(“the input  $x[n]$  is transformed by the system  $H$  into  $y[n]$ ”)



# Equations

- Usually, a system is described by the **input-output equation** (or **difference equation**) which explains how  $y[n]$  is defined in terms of  $x[n]$ .

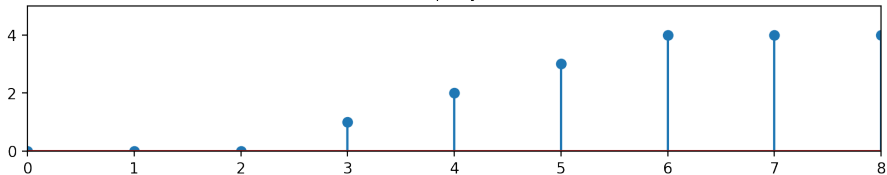
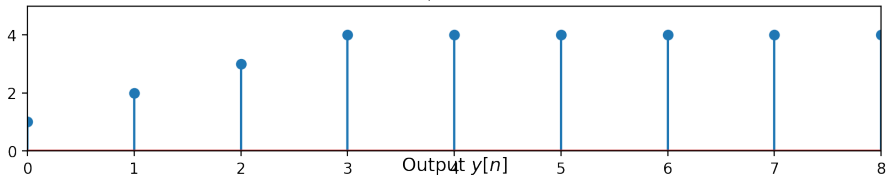
Examples:

1.  $y[n] = x[n]$  (the identity system)
2.  $y[n] = x[n - 3]$
3.  $y[n] = x[n + 1]$
4.  $y[n] = \frac{1}{3}(x[n + 1] + x[n] + x[n - 1])$
5.  $y[n] = \max(x[n + 1], x[n], x[n - 1])$
6.  $y[n] = (x[n])^2 + \log_{10} x[n - 1]$
7.  $y[n] = \sum_{k=-\infty}^n x[k] = x[n] + x[n - 1] + x[n - 2] + \dots$

# Example

$$y[n] = x[n - 3]$$

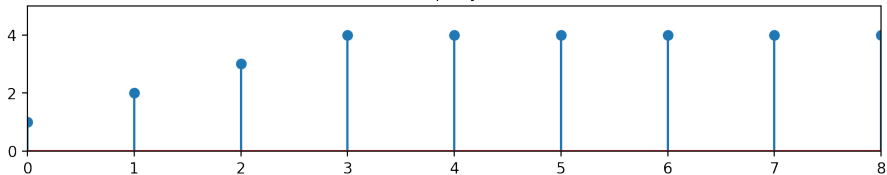
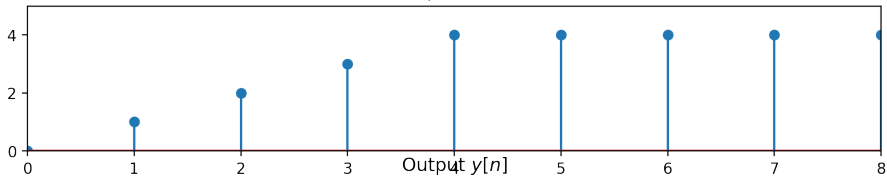
Input  $x[n]$



# Example

$$y[n] = x[n + 1]$$

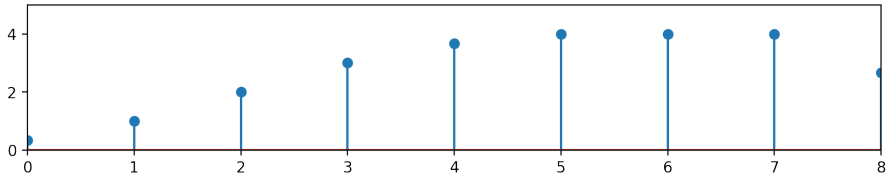
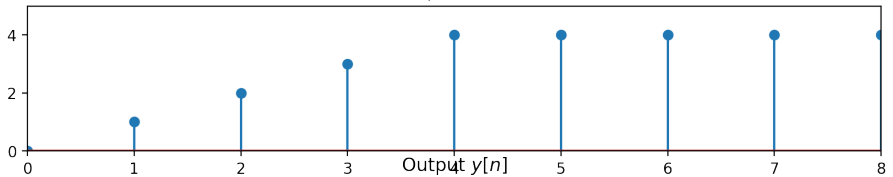
Input  $x[n]$



# Example

$$y[n] = (x[n+1] + x[n] + x[n-1])/3$$

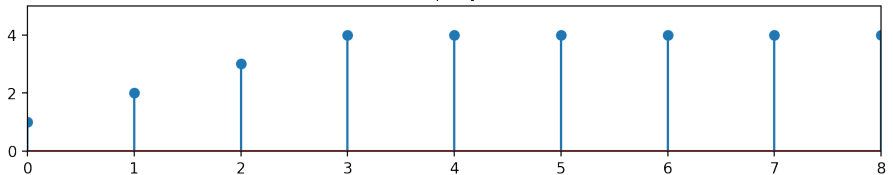
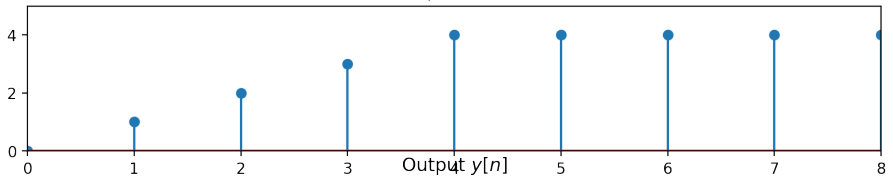
Input  $x[n]$



# Example

$$y[n] = \max(x[n+1], x[n], x[n-1])$$

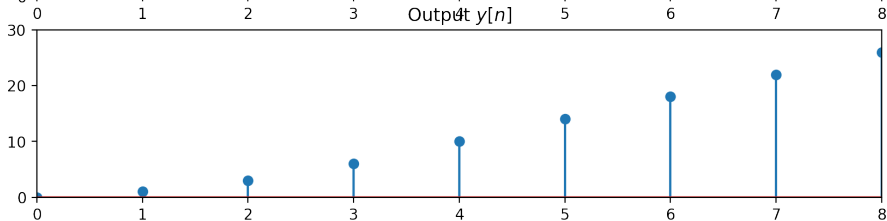
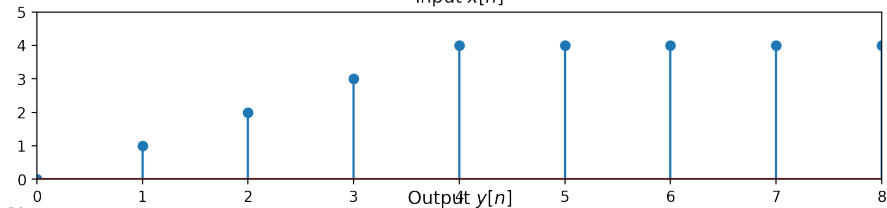
Input  $x[n]$



# Example

$$y[n] = \sum_{k=-\infty}^n x[k] = x[n] + x[n-1] + x[n-2] + \dots$$

Input  $x[n]$



# Recursive systems

- ▶ Some systems can/must be written in **recursive form**

$$y[n] = y[n - 1] + x[n],$$

- ▶ Must always specify **initial conditions**
  - ▶ i.e. initial value (e.g.  $y[-1] = 2.5$ )
  - ▶ if not mentioned, assume they are 0 (“relaxed system”)
  - ▶ they represent the internal state of the system at the starting moment
- ▶ For recursive systems, the output signal depends on both the input signal **and** on the initial conditions
  - ▶ different initial conditions lead to different outputs, even if input signal is the same
  - ▶ a recursive system with non-zero initial conditions can produce an output signal even in the absence of an input ( $x[n] = 0$ )

# Representation of systems

- ▶ The operation of a system can be described graphically (see examples on blackboard):
  - ▶ summation of two signals
  - ▶ scaling of a signal with a constant
  - ▶ multiplication of two signals
  - ▶ delay element
  - ▶ anticipation element
  - ▶ other blocks for more complicated math operations



## II.4 Classification of discrete systems

# Memoryless / systems with memory

- ▶ **Memoryless (or static)**: output at time  $n$  depends only on the input **from the same moment  $n$**
- ▶ Otherwise, the system **has memory (dynamic)**
- ▶ Examples:
  - ▶ memoryless:  $y[n] = (x[n])^3 + 5$
  - ▶ with memory:  $y[n] = (x[n])^3 + x[n - 1]$

# Memoryless / systems with memory

- ▶ Memory of size  $N$ :
  - ▶ output at time  $n$   $y[n]$  depends only up to the last  $N$  inputs,  $x[n - N], x[n - (N - 1)], \dots, x[n]$ ,
  - ▶ if  $N$  is finite: the system has **finite memory**
  - ▶ if  $N = \infty$ , the system has **infinite memory**
- ▶ Examples:
  - ▶ finite memory of order 4:  $y[n] = x[n] + x[n - 2] + x[n - 4]$
  - ▶ infinite memory:  $y[n] = 0.5y[n - 1] + 0.8x[n]$ 
    - ▶ recursive systems usually have infinite memory

# Memoryless / systems with memory

- ▶ An input sample has an effect on the output only for the next  $N$  time moments
- ▶ For systems infinite memory, any sample influences **all** the following samples, forever
  - ▶ but, if system is stable, the influence gets smaller and smaller

# Time-Invariant and Time-Variant systems

- ▶ A relaxed system  $H$  is **time-invariant** if and only if:

$$x[n] \xrightarrow{H} y[n]$$

implies,  $\forall x[n], \forall k$ , that

$$x[n-k] \xrightarrow{H} y[n-k]$$

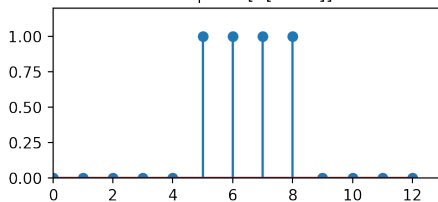
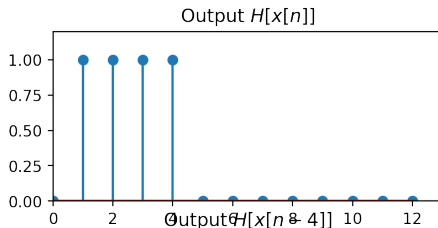
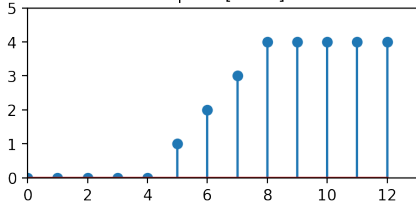
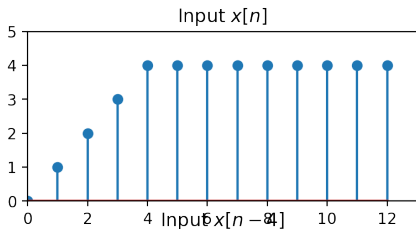
- ▶ Delaying the input signal with  $k$  will only delay the output with the same amount, otherwise the output is not affected
  - ▶ Must be true for all input signals, for all possible delays (positive or negative)
- ▶ Otherwise, the system is said to be **time-variant**

# Time-Invariant and Time-Variant systems

- ▶ Examples:
  - ▶  $y[n] = x[n] - x[n - 1]$  is time-invariant
  - ▶  $y[n] = n \cdot x[n]$  is not time-invariant
- ▶ A system is time-invariant if it depends on  $n$  only through the input signal  $x[n]$

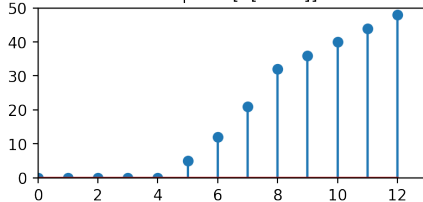
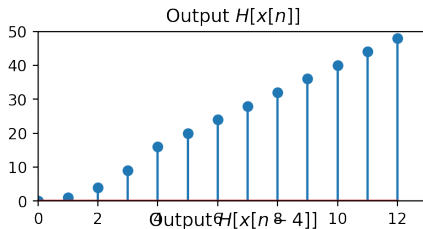
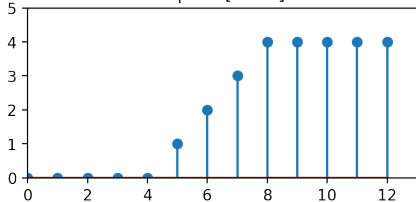
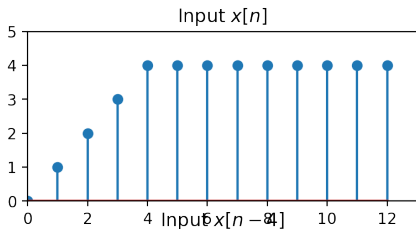
# Example

Time-invariant system  $y[n] = x[n] - x[n - 1]$



# Another example

Time-variant system  $y[n] = n \cdot x[n]$





# Linear and nonlinear systems

- ▶ A system  $H$  is **linear** if:

$$H[ax_1[n] + bx_2[n]] = aH[x_1[n]] + bH[x_2[n]].$$

- ▶ Composed of two parts:
  - ▶ Applying the system to a sum of two signals = applying the system to each signal, and adding the results
  - ▶ Scaling the input signal with a constant  $a$  is the same as scaling the output signal with  $a$
- ▶ The same relation will be true for a sum of many signals, not just two

# Linear and nonlinear systems

- ▶ Advantage of linear systems

- ▶ Complicated input signals can be decomposed into a sum of smaller parts
- ▶ The system can be applied to each part independently
- ▶ Then the results are added back

- ▶ Examples:

- ▶ linear system:  $y[n] = 3x[n] + 5x[n - 2]$
- ▶ nonlinear system:  $y[n] = 3(x[n])^2 + 5x[n - 2]$

# Linear and nonlinear systems

- ▶ For a system to be linear, the input samples  $x[n]$  must not undergo non-linear transformations.
- ▶ **The only transformations** of the input  $x[n]$  allowed to take place in a linear system are:
  - ▶ scaling (multiplication) with a constant
  - ▶ delaying
  - ▶ summing different delayed versions of the signal (not summing with a constant)

# Causal and non-causal systems

- ▶ **Causal:** the output  $y[n]$  depends only on the current input  $x[n]$  and the past values  $x[n-1]$ ,  $x[n-2]$ , ..., but not on the future samples  $x[n+1]$ ,  $x[n+2]$ , ...
- ▶ Otherwise the system is **non-causal**.
- ▶ A causal system can operate in real-time
  - ▶ we need only the input samples from the past
  - ▶ non-causal systems need samples from the future
- ▶ Examples:
  - ▶  $y[n] = x[n] - x[n-1]$  is causal
  - ▶  $y[n] = x[n+1] - x[n-1]$  is non-causal
  - ▶  $y[n] = x[-n]$  is non-causal

# Stable and unstable systems

- ▶ **Bounded** signal: if there exists a value  $M$  such that all the samples of the signal are smaller than  $M$ , in absolute values

$$x[n] \in [-M, M]$$

$$|x[n]| \leq M$$

- ▶ **Stable** system: if for any bounded input signal it produces a bounded output signal
  - ▶ not necessarily with the same  $M$
  - ▶ known as BIBO (Bounded Input  $\rightarrow$  Bounded Output)
- ▶ In other words: when the input signal has bounded values, the output signal does not go towards  $\infty$  or  $-\infty$ .

# Stable and unstable systems

► Examples:

►  $y[n] = (x[n])^3 - x[n + 4]$  is stable

►  $y[n] = \frac{1}{x[n] - x[n-1]}$  is unstable

►  $y[n] = \sum_{k=-\infty}^n x[k] = x[n] + x[n-1] + x[n-2] + \dots$  is unstable

Impulse response of Linear Time-Invariant (LTI) systems

# Linear Time-Invariant (LTI) systems

- ▶ Notation: An **LTI** system (**L**inear **T**ime-**I**nvariant) is a system which is simultaneously **linear** and **time-invariant**.
- ▶ LTI systems can be described via either (or both):
  1. the **impulse response**  $h[n]$
  2. the **difference equation**

$$\begin{aligned}y[n] &= - \sum_{k=1}^N a_k y[n-k] + - \sum_{k=1}^M b_k x[n-k] \\&= - a_1 y[n-1] - a_2 y[n-2] - \dots - a_N y[n-N] + b_0 x[n] + b_1 x[n-1] + \dots + b_M x[n-M]\end{aligned}$$



# The impulse response

- ▶ **Impulse response** of a system = output (response) of when the input signal is the impulse  $\delta[n]$ :

$$h[n] = H(\delta[n])$$

- ▶ The impulse response of a LTI system **fully characterizes the system**:
  - ▶ based on  $h[n]$  we can compute the response of the system to **any** input signal
  - ▶ all the properties of LTI systems can be described via characteristics of the impulse response

# Signals are a sum of impulses

- ▶ Any signal can be composed as **a sum of scaled and delayed impulses**  $\delta[n]$ .
- ▶ Example:  
 $x[n] = \{3, 1, -5, 0, 2\} = 3\delta[n] + \delta[n-1] - 5\delta[n-2] + 2\delta[n-2]$
- ▶ In general

$$x[n] = \sum_{k=-\infty}^{\infty} x[k]\delta[n-k]$$

i.e. a sum of impulses  $\delta[n]$ , delayed with  $k$  and scaled with the corresponding value  $x[k]$

# Convolution

- ▶ The response of a LTI system to a sum of impulses, delayed with  $k$  and scaled with  $x[k]$ , **is a sum of impulse responses, delayed with  $k$  and scaled with  $x[k]$ .**
  - ▶ The input signal is composed of separate impulses
  - ▶ LTI system  $\rightarrow$  each impulse will generate its own response
  - ▶ output signal is the sum of impulse responses, delayed and scaled

$$\begin{aligned}y[n] &= H(x[n]) \\&= H\left(\sum_{k=-\infty}^{\infty} x[k]\delta[n-k]\right) \\&= \sum_{k=-\infty}^{\infty} x[k]H(\delta[n-k]) \\&= \sum_{k=-\infty}^{\infty} x[k]h[n-k].\end{aligned}$$

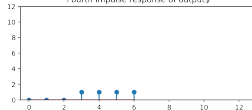
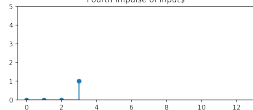
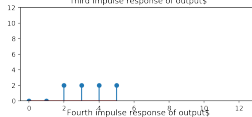
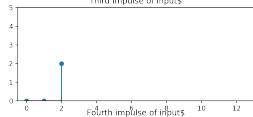
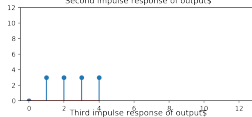
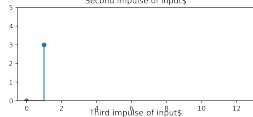
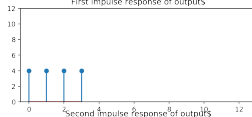
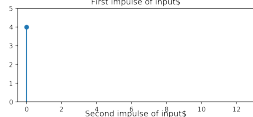
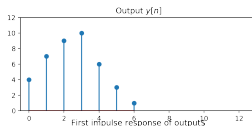
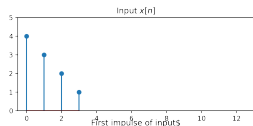
# Convolution

- ▶ This operation = the **convolution** of two signals  $x[n]$  and  $h[n]$

$$x[n] * h[n] = \sum_{k=-\infty}^{\infty} x[k]h[n-k]$$

- ▶ The response of a LTI system to an input signal  $x[n]$  is **the convolution of  $x[n]$  with the system's impulse response  $h[n]$**

# Example



# Properties of convolution

- Convolution is commutative (the order of the two signals doesn't matter):

$$x[n] * h[n] = \sum_{k=-\infty}^{\infty} x[k]h[n-k] = h[n] * x[n] = \sum_{k=-\infty}^{\infty} h[k]x[n-k]$$

Proof: make variable change  $(n-k) \rightarrow l$ , change all in equation

- Convolution is associative

$$(a[n] * b[n]) * c[n] = a[n] * (b[n] * c[n])$$

(No proof)

- The unit impulse is neutral element for convolution

# Interpretation of convolution equation

The convolution equation can be interpreted in two ways:

1. The output signal  $y[n]$  = a sum of a lot of impulse responses  $h[n]$ , each one delayed by  $k$  (hence  $[n - k]$ ) and scaled by  $x[k]$ 
  - ▶ one for each sample in the input signal
  - ▶ explain at blackboard

$$x[n] * h[n] = \sum_{k=-\infty}^{\infty} x[k]h[n - k]$$

# Interpretation of convolution equation

2. Each output sample  $y[n]$  = a weighted average of the input samples around it

▶  $y[n] = \dots + h[2] \cdot x[n-2] + h[1] \cdot x[n-1] + h[0] \cdot x[n] + h[n+1] \cdot x[n+1] + \dots$

- ▶ If  $h[n]$  has finite length (e.g. non-zero only between  $h[-2] \dots h[2]$ ), then there are only a few terms in the sum

- ▶ Example at blackboard

$$x[n] * h[n] = \sum_{k=-\infty}^{\infty} h[k]x[n-k]$$



# Properties of LTI systems expressed with $h[n]$

## 1. Identity system

- ▶ A system with  $h[n] = \delta[n]$  produces a response equal to the input,  $y[n] = x[n], \forall x[n]$ .
- ▶ Proof:  $\delta[n]$  is neutral element for convolution.

# Properties of LTI systems expressed with $h[n]$

## 2. Series connection is commutative

- ▶ LTI systems connected in series can be interchanged in any order
- ▶ Proof: by commutativity of convolution.
- ▶ LTI systems connected in series are equivalent to a single system with

$$h_{equiv}[n] = h_1[n] * h_2[n] * \dots * h_N[n]$$

# Properties of LTI systems expressed with $h[n]$

## 3. Parallel connection means sum

LTI systems connected in parallel are equivalent to a single system with

$$h_{equiv}[n] = h_1[n] + h_2[n] + \dots + h_N[n]$$

# Properties of LTI systems expressed with $h[n]$

## 4. Response of LTI systems to unit step

- ▶ If the input signal is  $u[n]$ , the response of the system is

$$s[n] = u[n] * h[n] = h[n] * u[n] = \sum_{k=-\infty}^{\infty} h[k]u[n-k] = \sum_{k=-\infty}^n h[k]$$

# Properties of LTI systems expressed with $h[n]$

## ► Proof:

- The signal  $\sum_{k=-\infty}^n h[k]$  is a *discrete-time integration* of  $h[n]$
- The unit step  $u[n]$  itself is the discrete-time integral of the unit impulse:

$$u[n] = \sum_{k=-\infty}^n \delta[k]$$

$$\delta[n] = u[n] - u[n-1]$$

- Therefore the system response to the integral of the impulse = the integral of the system response to the impulse
- The interchanging of the integration with the system is due to the linearity of the system and is valid for all signals:

$$H\left(\sum_{k=-\infty}^n x[k]\right) = \sum_{k=-\infty}^n H(x[k])$$

Relation between LTI system properties and  $h[n]$

# 1. Causal LTI systems and their $h[n]$

If a LTI system is causal, then

$$h[n] = 0, \forall n < 0$$

► Proof:

- $y[n] = \sum_{k=-\infty}^{\infty} x[k]h[n-k]$ ,
- $y[n]$  does not depend on  $x[n+1], x[n+2], \dots$
- it means that these terms are multiplied with 0
- the value  $x[n+1]$  is multiplied with  $h[n-(n+1)] = h[-1]$ ,  $x[n+2]$  is multiplied with  $h[n-(n+2)] = h[-2]$ , and so on
- Therefore:

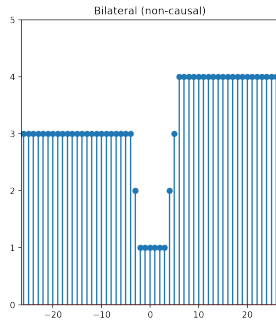
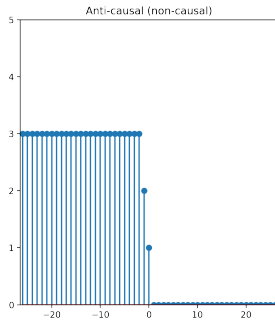
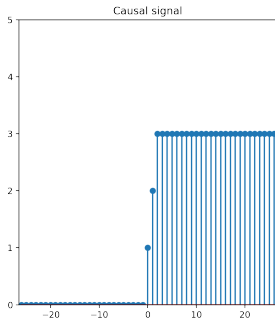
$$h[n] = 0, \forall n < 0$$

# Causal signals and causal systems

- ▶ A signal which is 0 for  $n < 0$  is called a *causal signal*
- ▶ Otherwise the signal is *non-causal*
- ▶ We can say that *a system is causal if and only if it has a causal impulse response*
- ▶ Further definitions:
  - ▶ a signal which 0 for  $n > 0$  is called an *anti-causal* signal
  - ▶ a signal which has non-zero values both for some  $n > 0$  and for some  $n < 0$  (and thus is neither causal nor non-causal) is called *bilateral*.



# Example



## 2. Stable systems and their $h[n]$

- ▶ Considering a bounded input signal,  $|x[n]| \leq A$ , the absolute value of the output is:

$$\begin{aligned}|y[n]| &= \left| \sum_{k=-\infty}^{\infty} x[k]h[n-k] \right| \\ &\leq \sum_{k=-\infty}^{\infty} |x[k]h[n-k]| \\ &= \sum_{k=-\infty}^{\infty} |x[k]| |h[n-k]| \\ &\leq A \sum_{k=-\infty}^{\infty} |h[n-k]| \end{aligned}$$

- ▶ Therefore **a LTI system is stable if**

$$\sum_{k=-\infty}^{\infty} |h[n]| < \infty$$

### 3. Memoryless systems and their $h[n]$ (Exercise)

#### Exercises:

- ▶ What can we say about the impulse response  $h[n]$  of a memoryless system?
- ▶ What about a system with finite memory  $M$ ?

## FIR and IIR systems

# Support

- ▶ The **support** of a discrete signal = the smallest interval of  $n$  such that the signal is 0 everywhere outside the interval.
- ▶ Examples: at whiteboard
- ▶ Depending on the support of the impulse response, discrete LTI systems can be **FIR** or **IIR** systems.

# FIR systems

- ▶ A **Finite Impulse Response (FIR)** system has an impulse response with finite support
  - ▶ i.e. the impulse response is 0 outside a certain interval.
- ▶ For a causal system:
  - ▶  $h[n] = 0$  for  $n < 0$
  - ▶ therefore  $h[n] = 0$  for  $n < 0$  or  $n \geq M$ , for some  $M$
  - ▶ The convolution becomes:

$$y[n] = \sum_{k=0}^M h[k]x[n-k] = h[0] \cdot x[n] + h[1] \cdot x[n-1] + \dots h[M] \cdot x[n-M]$$

- ▶ For a causal FIR system, the output is a linear combination of the last  $M$  input samples (has finite memory  $M$ )

- ▶ An **I**nfinite **I**mpulse **R**esponse (**FIR**) system has an impulse response with infinite support
  - ▶ i.e. the impulse response never becomes completely 0 forever.
- ▶ Causal system: the output  $y[n]$  potentially depends on all the preceding input samples
  - ▶ from the convolution equation
- ▶ An IIR system has infinite memory

## Recursive / non-recursive implementations

- ▶ **Recursive** implementation: compute  $y[n]$  based partly on the previous output samples  $y[n-1], y[n-2], \dots$ 
  - ▶ more efficient
- ▶ For a recursive LTI system, the output  $y[n]$  depends on:
  - ▶ the last  $N$  samples of the output,  $y[n-1], \dots, y[n-N]$
  - ▶ and the current and the last  $M$  samples of the input,  $x[0], x[1], \dots, x[n-M]$ .
- ▶ Example:

$$y[n] = \frac{1}{n+1} \sum_0^n x[n]$$

can be rewritten in recursive form:

$$y[n] = n \cdot y[n-1] + x[n]$$



## Recursive / non-recursive implementations

- ▶ **Non-recursive** system: the output  $y[n]$  is computed based only on last  $M$  samples of the input,  $x[0]$ ,  $x[1]$ ,  $\dots$   $x[n-M]$ .
- ▶ FIR systems can always be implemented non-recursively, but may also be implemented in a recursive way
- ▶ IIR systems can only be implemented recursively
  - ▶ otherwise they would need infinite memory

# Initial conditions for recursive systems

- ▶ Recursive systems rely on previous outputs  $\rightarrow$  the previous values must be always available
- ▶ We need some starting values at the start moment (**the initial conditions** of the system)
- ▶ Notes:
  - ▶ Output signal depends on the input **and** on the initial conditions
  - ▶ A system with non-zero initial conditions produces an output even when the input signal is zero
  - ▶ This output is called *zero-input response*,  $y_{zi}[n]$
  - ▶ A system with initial conditions equal to 0 is called *relaxed*
  - ▶ The output of a relaxed system to an input signal is called *zero-state response*,  $y_{zs}[n]$  (also called *forced response*)
- ▶ For linear systems, the output of a system is always the sum of the forced response and the natural response:

$$y[n] = y_{zs}[n] + y_{zi}[n]$$