SIGNALS AND SYSTEMS USING MATLAB
Chapter 0 — From the Ground Up!

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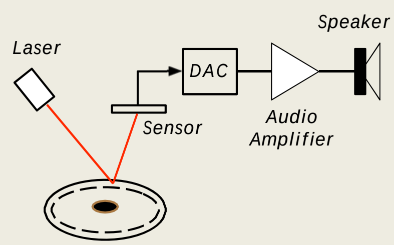
Digital signal processing

- 1948 – birth of digital technologies
  - Transistor (Bell Labs)
  - Stored–program computer (Manchester University, UK)
  - Publications
    - Shannon's digital communications
    - Hamming's error correcting codes
    - Wiener's Cybernetics
- Moore's Law, DSPs and FPGAs
  - 1965 — Moore (Intel): number of transistors in a chip would double every 2 years
  - Digital Signal Processors (DSPs): optimized microprocessors for real–time processing
  - Field Programmable Gate Array (FPGA): device with programmable blocks and interconnects

Compact disc (CD) and compact disc player



When playing a CD, the CD player follows tracks in the disc, focus laser beam on them, as CD is spun. Light is reflected by pits and bumps on the surface of disc (corresponding to the coded digital signal from acoustic signal). Sensor detects reflected light and converts it into a digital signal and converted into an analog signal by DAC. Amplified and fed to speakers signal sounds like original recorded acoustic signal.

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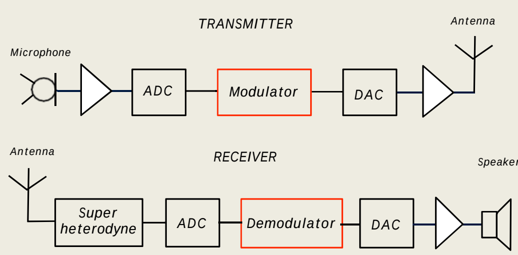
Software–defined radio (SDR)



Voice SDR mobile two-way radio
Transmitter: voice signal inputted using microphone, amplified by an audio amplifier, converted into a digital signal by ADC,modulated using software, converted by DAC into analog signal which is amplified and radiated by antenna
Receiver: analog signal received by antenna is processed by a superheterodyne, converted by ADC,demodulated using software, converted by DAC, amplified and fed to speaker

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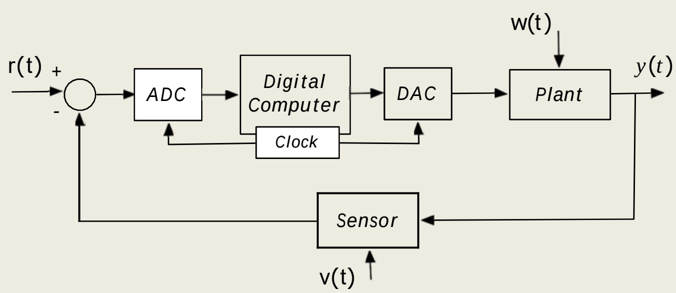
Computer–control system



Computer control system for an analog plant (e.g., cruise control for a car)
Reference signal r (t) (e.g., desired speed) and output y (t) (e.g., car speed)
Signals v (t) and w(t): disturbances or noise in plant and sensor (e.g., electronic noise in the sensor and undesirable vibration in the car)

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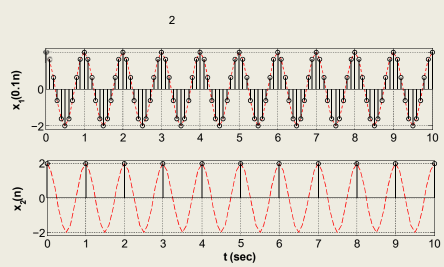
Continuous and discrete representations

Sampling continuous–time signal x (t) into discrete–time signal sequence x [n]:

$$x[n] = x(nTs) = x(t)|_{t=nTs}$$

Ts :sampling perioddepends on frequency content of x (t)



Sampling x (t) = 2 cos(2πt), 0 ≤ t ≤ 10, with Ts1 = 0.1 (top) and Ts2 = 1 (bottom) giving x1(0.1n) = x1[n] and x2(n) = x2[n]
Notice similarity between x1[n] and x (t) and loss of information when Ts2 = 1

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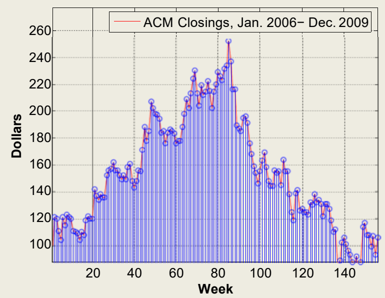
Inherent discrete–time signal



Weekly closings of ACM stock for 160 weeks in 2006 to 2009. ACM is the trading name of the stock of the imaginary company ACME Inc. makers of everything you can imagine.

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Implementation of DSP Algorithms

- Continuous-time signals → Electrical and electronic circuits
- Digital signals → Addition, multiplication, and delay
- DSP system's output → Arithmetic operations on input
- Possible real-time implementations;
  - General-purpose microprocessors (Ps) and micro-controllers (Cs)
  - General-purpose digital signal processors (DSPs)
  - Field programmable gate arrays (FPGAs)

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Infinitesimal and finite calculus

- Derivative and forward– difference

Derivative: rate of change of $x(t)$

$$D[x(t)] = \frac{dx(t)}{dt} = \lim_{h \to 0} \frac{x(t+h) - x(t)}{h}$$

Forward–difference: difference between $x((n+1)T_s)$ and $x(nT_s)$

$$\Delta[x(nT_s)] = x((n+1)T_s) - x(nT_s)$$

- Integral and summation

Integral and derivative

$$I(t) = \int_{t_0}^{t} x(\tau)d\tau, \quad x(t) = \frac{dI(t)}{dt}$$

Integral and summation

$$I(t) \approx \sum_n x(nT_s)p(n), \quad p(n) \text{ pulses of width } T_s$$

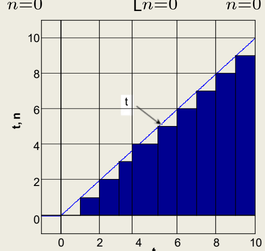
Approximation of integral

Area of $x(t) = t,\ 0 \leq t \leq 10$, and 0 otherwise

$$I(t) = \int_0^{10} t \ \ dt = \frac{t^2}{2}\,\Big|_{t=0}^{10} = 50$$

approximate $x(t)$ by aggregation of pulses $p[n]$ of width $T_s = 1$ and height $nT_s = n$

$$I(t) \approx \sum_{n=0}^{9} p[n] = \sum_{n=0}^{9} n = 0.5\left[\sum_{n=0}^{9} n + \sum_{n=0}^{9}(9-n)\right] = \frac{10 \times 9}{2} = 45$$



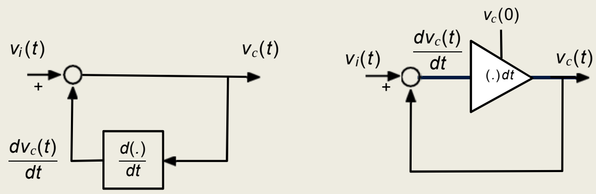
Differential and difference equations

Solve d.e. from series RC circuit with a constant voltage source vi (t) as input and R = 1 Ω, C = 1 F (huge plates!)

$$vi\ (t) = vc\ (t) + \frac{dv_c(t)}{dt} \qquad t \geq 0$$

with initial voltage vc (0) across capacitor

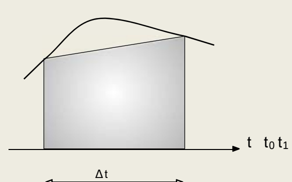
- Use integrators



Block diagram for d.e. using differentiators (left) and integrators (right). Differentiators increase noise, integrators smooth out noise

Approximate integral

$$v_c(t) = \int_0^t [v_i(\tau) - v_c(\tau)]d\tau + v_c(0) \qquad t \geq 0$$



Trapezoidal approximation of area

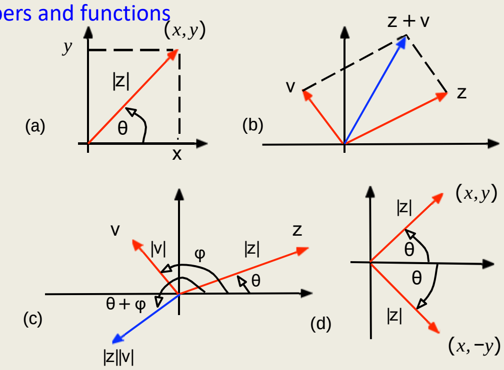
- Difference equation

$$v_c(nT) = \frac{T}{2+T}[v_i(nT) + v_i((n-1)T)] + \frac{2-T}{2+T}v_c((n-1)T), \quad v_c(0) = 0, \quad n \geq 1$$

can be solved iteratively

Complex or real?

- Damping and frequencyof signals represented by complex variable
- Complex numbers and functions



(a) z = x + jy as vector ; (b) addition of complex numbers; (c) multiplication of complex numbers; (d) complex conjugation of z.

Complex numbers

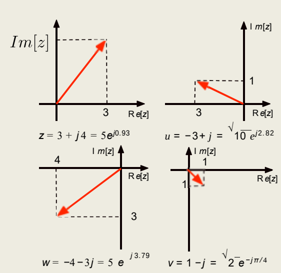
- Representations

  z = x + jy rectangular
  = |z| $e^{j\angle z}$ polar

- Operations $z = x + jy = |z|e^{j\angle(z)}, \quad v = u + jw = |v|e^{j\angle(v)}$

$$\text{Addition/subtraction:} \quad z + v = (x+u) + j(y+w) \quad \text{rectangular}$$
$$\text{Multiplication/division:} \quad zv = |z||v|e^{j(\angle(z)+\angle(v))} \quad \text{polar}$$
$$\text{Conjugation} \quad z^* = x - jy = |z|e^{-j\angle z}$$

  - Rectangular to polar conversion



Euler's identity

$$\boxed{e^{j\theta} = \cos(\theta) + j\sin(\theta)}$$

$$\cos(\theta) = \mathrm{Re}[e^{j\theta}] = \frac{e^{j\theta} + e^{-j\theta}}{2}$$

$$\sin(\theta) = \mathrm{I}m[e^{j\theta}] = \frac{e^{j\theta} - e^{-j\theta}}{2j}.$$

- Polar to rectangular conversion

$$\begin{aligned}
z &= \sqrt{2}e^{j\pi/4} = \sqrt{2}\cos(\pi/4) + j\sqrt{2}\sin(\pi/4) = 1 + j, \quad \text{(first quadrant)} \\
u &= \sqrt{2}e^{-j\pi/4} = \sqrt{2}\cos(-\pi/4) + j\sqrt{2}\sin(-\pi/4) = \sqrt{2}\cos(\pi/4) - j\sqrt{2}\sin(\pi/4) \\
&= 1 - j, \quad \text{(fourth quadrant)} \\
w &= 5e^{j190^o} = 5e^{j180^o}e^{j10^o} = -5\cos(10^o) - j5\sin(10^o) \\
&= -4.92 - j0.87, \quad \text{(third quadrant)}
\end{aligned}$$

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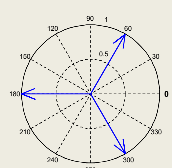
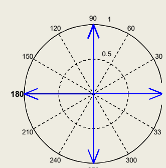
- Roots and powers of j

$$z^3 + 1 = 0 \quad \Rightarrow \quad z_k^3 = -1 = e^{j(2k+1)\pi}, k = 0, 1, 2$$

$$z_k = e^{j(2k+1)\pi/3}, \ k = 0, 1, 2$$

$$z_0 = e^{j\pi/3}, \quad z_1 = e^{j\pi} = -1, \quad z_2 = e^{j(6-1)\pi/3} = e^{j2\pi}e^{-j\pi/3} = e^{-j\pi/3}$$





Left: roots of $z^3 + 1 = 0$. Right: integer powers of j, periodic of period 4, with period of $\{1, j, -1, -j\}$

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- Trigonometric identities

$$\sin(-\theta) = \frac{e^{-j\theta} - e^{j\theta}}{2j} = -\sin(\theta)$$
$$\cos(\pi + \theta) = e^{j\pi}\frac{e^{j\theta} + e^{-j\theta}}{2} = -\cos(\theta)$$
$$\cos^2(\theta) = \left[\frac{e^{j\theta} + e^{-j\theta}}{2}\right]^2 = \frac{1}{4}[2 + e^{j2\theta} + e^{-j2\theta}] = \frac{1}{2} + \frac{1}{2}\cos(2\theta)$$
$$\sin(\theta)\cos(\theta) = \frac{e^{j\theta} - e^{-j\theta}}{2j}\,\frac{e^{j\theta} + e^{-j\theta}}{2} = \frac{e^{j2\theta} - e^{-j2\theta}}{4j} = \frac{1}{2}\sin(2\theta).$$

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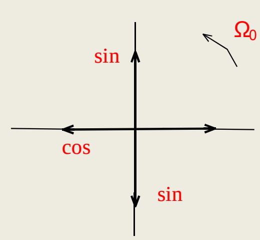
Phasors

- Sinusoids and phasors

$x(t) = A\cos(\Omega_0 t + \psi) \qquad -\infty < t < \infty$

A amplitude, $\Omega_0 = 2\pi f_0$ frequency (rad/sec), ψ phase (rad)

$\boxed{\text{Phasor}: X = Ae^{j\psi},\ x(t) = \text{Re}[Xe^{j\Omega_0 t}]}$



Generation of sinusoids from phasors of a frequency Ω_0 shown at initial position
https://lpsa.swarthmore.edu/BackGround/phasor/phasor.html

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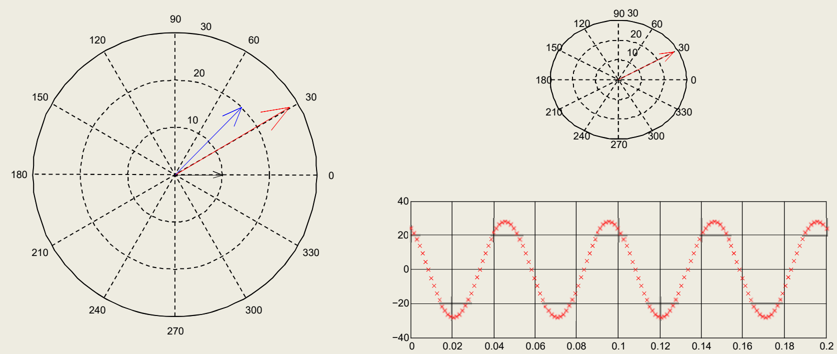


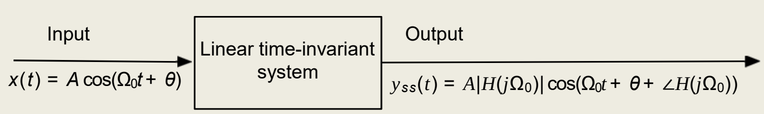
Sum of phasors $I_1 = 10e^{j0}$ and $I_2 = 20e^{j\pi/4}$ with the result in the top left and the corresponding sinusoid (right bottom).

Phasors and systems

- Eigenfunction property of LTI systems

$$\text{Input: } x(t) = \text{Re}[Xe^{j\Omega_0 t}], \text{ input phasor } X = Ae^{j\theta}$$
$$\text{Output: } y(t) = \text{Re}[Ye^{j\Omega_0 t}], \text{ output phasor } Y = XH(j\Omega_0)$$

- Steady–state response



Frequency response of system

$$H(j\Omega_0) = |H(j\Omega_0)|e^{\angle H(j\Omega_0}$$