Signals & Systems

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CONTENTS

CHAPTER 1

DISCRETE TIME SYSTEMS

1.1 INTRODUCTION

Definition 1.1 (Signal).

A signal is a function. That is, for some signal x we take as input an element from $\mathbb{R}$ or $\mathbb{Z}$ and output either a $\mathbb{R}$ or $\mathbb{C}$ number.

- Put simply, signals follow the funcition rule that tells us what mapping the function in question should follow.
- From this, we abide by the convention that whenever the domain of our signal is $\mathbb{Z}$ we are working in discrete time. Conversely, if the domain is $\mathbb{R}$ we will be in continuous time.

Definition 1.2 (Kronecker Delta a.k.a. Discrete Time Impulse).

$$\delta(n) = \begin{cases} 1, & \text{if } n = 0 \\ 1, & \text{if } n < 0 \end{cases}.$$

Definition 1.3 (Discrete Time Unit Step).

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

Definition 1.4 (Continuous Time Unit Step).

$$u(t) = \begin{cases} 1, & \text{if } t \geq 0 \\ 0, & \text{if } t < 0 \end{cases}.$$

Theorem 1.1. Any discrete time signal can be decomposed into a linear combination of shifted impulses. It follows that, the unit step function can be reinterpreted as

$$u(n) = \sum_{k=0}^{\infty} \delta(n-k).$$

Theorem 1.2. Immediately from above, we say that any discrete time signal can be expressed as a linear combination of shifted impulses.

$$u(n) = \sum_{k=0}^{\infty} \delta(n-k) = \sum_{m=-\infty}^{n} \delta(m).$$

- In discrete time, the unit step is the cumulative sum of Kronecker deltas. A similar concept to that of the integral.
- We can represent $\delta(n)$ in terms of shifted $u(n)$'s as

$$\delta(n) = u(n) - u(n-1).$$

Note that
$$\delta(n) = \frac{u(n) - u(n-1)}{n - (n-1)} = u(n) - u(n-1).$$

It suffices to say that this is similar to the derivative.

- Therefore, in discrete time $\delta(n)$ is known as the discrete time derivative of the impulse signal and $u(n)$ is it's integral.

1.2 LTI Systems & Impulse Response

Definition 1.5 (Systems).

Similar to signals we say that systems are functions. That is, $x \longrightarrow H \longrightarrow y$ where x is our input signal and y is the corresponding output signal after x "passes" through the system H.

More formally, we define $\mathbb{X}$ to be the input signal space and $\mathbb{Y}$ to be the output signal space. Thus, $y = H(x)$ where $x \in \mathbb{X},\ y \in \mathbb{Y}$.

- **Systems Properties:** (1) Linearity (or Superposition) and (2) Time Invariance.
- **Linearity:** System H is said to be linear if it satisfies both the scaling and additivity property.
  1. Scaling: The output of a weighted input must be scaled by the weight of that input, i.e., $\alpha x \longrightarrow H \longrightarrow \alpha y,\ \forall x \in \mathbb{X},\ \forall \alpha \in \mathbb{R}/\mathbb{C}$.
  2. Additivity: The system is additive if it satisfies the below,

$$x_1 \longrightarrow H \longrightarrow y_1 \quad \text{and} \quad x_2 \longrightarrow H \longrightarrow y_1 \quad \text{then} \quad x_1 + x_2 \longrightarrow H \longrightarrow y_1 + y_2$$

  for all $x_1, x_2 \in \mathbb{X}$.

  The notion of **superposition** occurs when the scaling and additive properties are combined in one step, i.e.,
$$\alpha x_1 + \beta x_2 \longrightarrow H \longrightarrow \alpha y_1 + \beta y_2$$
  for all $\alpha, \beta \in \mathbb{R}/\mathbb{C}$ and for all $x_1, x_2 \in \mathbb{X}$.

- **Time Invariance:** If input $\hat{x}(n) = x(n-N)$ for $N \in \mathbb{Z}$, then if $\hat{y}(n) = y(n-N),\ \forall x \in \mathbb{X}$ and $\forall N \in \mathbb{Z}$, the system H is time invariant.
- **Zero Input - Zero Output (ZIZO):** If our input is zero then the output must be zero, and if this does not hold then the system is nonlinear.
- **LTI Systems:** Are systems that possess both linearity and time invariance.

- If the input signal $x(n) = \delta(n)$, then $y(n) \triangleq h(n)$ where $h(n)$ is called the **impulse response** of the system.

Theorem 1.3. Given that we now the impulse response of an LTI system, we then know the system response to any arbitrary input x.

Proof.

$$\begin{aligned} \delta(n) &\longrightarrow H \longrightarrow h(n) \\ \delta(n-k) &\longrightarrow H \longrightarrow h(n-k) \\ x(k)\delta(n-k) &\longrightarrow H \longrightarrow x(k)h(n-k) \\ \sum_{k=-\infty}^{\infty} x(k)\delta(n-k) &\longrightarrow H \longrightarrow \sum_{k=-\infty}^{\infty} x(k)h(n-k) \end{aligned}$$

where $x(n) = \sum_{k=-\infty}^{\infty} x(k)\delta(n-k)$ and $y(n) = \sum_{k=-\infty}^{\infty} x(k)h(n-k)$. ∎

- **DT-LTI Systems:** Are a result of the above proof,

$$x(n) \longrightarrow H \longrightarrow y(n) = \sum_{k=-\infty}^{\infty} x(k)h(n-k)$$

  where we define y to be the convolution between x and h,

$$y(n) = (x * h)(n) = \sum_{k=-\infty}^{\infty} x(k)h(n-k). \tag{1.1}$$

- Convolution is commutative:

$$\begin{aligned} y(n) &= (x * h)(n) \\ &= \sum_{k=-\infty}^{\infty} x(k)h(n-k) \\ &= \sum_{m=-\infty}^{\infty} x(n-m)h(m) \\ &= (h * x)(n) \end{aligned}$$

- If $x(n) \longrightarrow F \longrightarrow G \longrightarrow y(n)$, then we define an intermediate signal $q(n) = (x * f)(n)$. Then, $y(n) = (q * g)(n) = (x * f * g)(n) = (x * h)(n)$ where $h(n) = (f * g)(n)$ is the impulse response of a "bigger" system H.
- Two systems in series (cascaded) is an LTI system.
- $\delta(n)$ also referred as the identity element in discrete time, and $(\delta * h)(n) = (h * \delta)(n) = h(n)$.
- **Euler's Formula**: $e^{i\theta} = \cos\theta + i\sin\theta$.

- **Inverse Euler's Formula:**

$$\cos\theta = \frac{e^{i\theta} + e^{i\theta}}{2} \tag{1.2}$$

$$\sin\theta = \frac{e^{i\theta} - e^{-i\theta}}{2i} \tag{1.3}$$

- **Frequency Response of an LTI System:** From previous observations we know the following two facts:

$$x(n) = \delta(n) \longrightarrow H \longrightarrow y(n) = h(n)$$

where $x(n)$ is "activated" only when $n = 0$ and more generally,

$$x(n) \longrightarrow H \longrightarrow y(n) = (x * h)(n).$$

If $x(n)$ were to be "active" for every time value of n, then

$$x(n) = e^{i\omega n} \longrightarrow H \longrightarrow y(n)$$

where

$$\begin{aligned} y(n) &= (x * h)(n) \\ &= \sum_{k=-\infty}^{\infty} e^{i\omega k} h(n-k) \\ &= e^{i\omega n} \sum_{m=-\infty}^{\infty} h(m) e^{-i\omega m}. \end{aligned}$$

The term $\sum_{m=-\infty}^{\infty} h(m)e^{-i\omega m}$ is a constant that only depends on ω. Thus, the frequency response of the system is,

$$H(\omega) \triangleq \sum_{m=-\infty}^{\infty} h(m) e^{-i\omega m}. \tag{1.4}$$

- Similar idea to eigenvalues, $A\vec{x} = \lambda\vec{x}$, where A is the system response, $H(\omega)$ is the eigenvalue, and our complex exponential is $\vec{x}$.
- Think of $H(\omega)$ as a scaling object.
- **Eigenfunction Property:** Denote our input signal as the complex exponential $e^{i\omega n}$ which is the eigenfunction with respect to the DT-LTI system. It follows that,

$$e^{i\omega n} \longrightarrow H \longrightarrow H(\omega)e^{i\omega n}.$$

- Note that a large class of signals of interest can be written as a linear combination of complex exponentials (Fourier Analysis).

- The frequency response of a DT-LTI system is 2π periodic,

$$H(\omega + 2\pi) = \sum_{n=-\infty}^{\infty} h(n)e^{-i(\omega+2\pi)n} = \sum_{n=-\infty}^{\infty} h(n)e^{-i\omega n}.$$

  When analyzing the frequency response of a system only focus on $\omega \in (0, 2\pi)$ or $\omega \in (-\pi, \pi)$.

- More generally, $H(\omega)$ is $2\pi n$ periodic $\forall\ n \in \mathbb{Z}$.

- From above, $H(\omega)$ has fundamental period 2π.

1.3 BIBO Stability, Causality, & Periodicity

- **Periodicity of Complex Exponentials:** For a given continuous time signal $e^{i\omega t}$, it experiences $\frac{2\pi}{\omega}$ revolutions per second, then ω denotes the radians per second of the signal.

Theorem 1.4 (Continuous Time Periodicity)**.**

We say that, $x : \mathbb{R} \to \mathbb{R}$ is T periodic if $\exists\ T$ s.t. $x(t+T) = x(t),\ \forall t \in \mathbb{R}$.

- Smallest such positive t is called the **fundamental period** in continuous time.

- The **fundamental frequency** is given by $f_0 = \frac{1}{T}$ and $\omega = \frac{2\pi}{T}$ has units of fundamental frequency, i.e., $\omega_0 = 2\pi f_0$.

- $e^{i\omega t}$ is periodic in t with fundamental period $T = \frac{2\pi}{\omega}$, thus it is not periodic in ω.

Theorem 1.5 (Discrete Time Periodicity)**.**

Say that $x : \mathbb{Z} \to \mathbb{R}$ is N periodic if $\exists\ N$ s.t. $x(n+N) = x(n),\ \forall\ n \in \mathbb{Z}$.

- Small such positive N is the fundamental period in discrete time.

- $f_0 = \frac{1}{N}$ is the fundamental frequency in discrete time and $\omega = \frac{2\pi}{N}$ has units of fundamental frequency, i.e., $\omega_0 = w\pi f_0$.

- $e^{i\omega n}$ is periodic in ω with fundamental period 2π, i.e., it is only periodic in n if ω is a rational multiple of π:

$$\begin{aligned} e^{i\omega(n+N))} &= e^{i\omega n} \\ e^{i\omega N} &= 1 \\ \omega N &= 2\pi k \\ \omega &= \frac{2\pi k}{N} \\ &= (\frac{2\pi}{N})k \end{aligned}$$

  therefore ω must be a rational multiple.

1.4 Discrete Time Difference Equations

- **Finite Impulse Response:** Example is the two point moving average filter,

  $$y(n) = \frac{1}{2}x(n) + \frac{1}{2}x(n-1)$$

  with corresponding impulse response $h(n) = \frac{\delta(n)+\delta(n-1)}{2}$.

- **Infinite Impulse Response:** Example is the exponentially weighted average filter,

  $$y(n) = x(n) + \alpha y(n-1)$$

  with impulse response $h(n) = \alpha^n u(n)$.

1.5 Discrete Time State Space Representation

Chapter 2

Continuous Time Systems

Chapter 3

Frequency Analysis

3.1 Discrete Time Fourier Series

3.2 Continuous Time Fourer Series

3.3 Discrete Time Fourier Transform

3.4 Continuous Time Fourier Transform

Chapter 4

Sampling and Modulation

4.1 Modulation

4.2 Sampling Theorem

4.3 Z-Transform

4.4 Laplace Transform