

# GATE EC 2017- Q.7

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## Question

The input  $x(t)$  and output  $y(t)$  of a continuous time signal are related as:

$$y(t) = \int_{t-T}^t x(u) du \quad (1)$$

The system is:

- ① Linear and Time-variant
- ② Linear and Time-invariant
- ③ Non-Linear and Time-variant
- ④ Non-Linear and Time-invariant

# Linear Systems and Time Invariant Systems

## Definition

We say that a system is **linear** if and only if it follows the Principle of Superposition, i.e Law of Additivity and Law of Homogeneity.

## Definition

A system is said to be **time invariant** if the output signal does not depend on the absolute time, i.e a time delay on the input signal directly equates to the delay in the output signal.

# Lemma

## Lemma

*The system relating the input signal  $x(t)$  and output signal  $y(t)$ , given by*

$$y(t) = \int_{t-T}^t x(u) du \quad (2)$$

*is linear and time invariant in nature.*

## Proof: Law of Additivity

Let the input signals be  $x_1(t)$  and  $x_2(t)$ , and their corresponding output signals be  $y_1(t)$  and  $y_2(t)$ , then:

$$y_1(t) = \int_{t-T}^t x_1(u) du \quad (3)$$

$$y_2(t) = \int_{t-T}^t x_2(u) du \quad (4)$$

$$y_1(t) + y_2(t) = \int_{t-T}^t [x_1(u) + x_2(u)] du \quad (5)$$

## Proof: Law of Additivity

Now, consider the input signal of  $x_1(t) + x_2(t)$ , then the corresponding output signal is given by  $y'(t)$ :

$$y'(t) = \int_{t-T}^t [x_1(u) + x_2(u)] du \quad (6)$$

Clearly, from (5) and (6):

$$y'(t) = y_1(t) + y_2(t) \quad (7)$$

Thus, the Law of Additivity holds.

## Proof: Law of Homogeneity

Consider an input signal  $kx(t)$ , where  $k$  is any constant. Let the corresponding output be given by  $y'(t)$ , then:

$$y'(t) = \int_{t-T}^t kx(u) du \quad (8)$$

$$= k \int_{t-T}^t x(u) du \quad (9)$$

$$= ky(t) \quad (10)$$

Clearly, from (10),

$$y'(t) = ky(t) \quad (11)$$

Thus, the Law of Homogeneity holds.

# Proof

Since both the Laws hold, the system satisfies the Principle of Superposition, and is thus, a **linear system**.



## Proof: Time Invariance

To check for time-invariance, we would introduce a delay of  $t_0$  in the output and input signals.

Delay in output signal:

$$y(t - t_0) = \int_{t-t_0-T}^{t-t_0} x(u) du \quad (12)$$

## Proof: Time Invariance

Now, we consider an input signal with a delay of  $t_0$ , given by  $x(t - t_0)$ , and let the corresponding output signal be given by  $y'(t)$ , then:

$$y'(t) = \int_{t-T}^t x(u - t_0) du \quad (13)$$

Substituting  $a = u - t_0$ :

$$y'(t) = \int_{t-t_0-T}^{t-t_0} x(a) da \quad (14)$$

Clearly, from (12) and (14):

$$y'(t) = y(t - t_0) \quad (15)$$

Thus, the system is **time-invariant**.

Thus, **2) Linear and Time- invariant** is the correct answer.

# Impulse response

Since the given system is an LTI system, it would possess an impulse response  $h(t)$ , which is the output of the system when the input signal is the Impulse function, given by  $\delta(t)$ . Thus,

$$h(t) = \int_{t-T}^t \delta(u) du \quad (16)$$

# Impulse function

The Impulse function can be loosely defined as:

$$\delta(t) = \begin{cases} \infty & t = 0 \\ 0 & \text{otherwise} \end{cases} \text{ and } \int_{-\infty}^{\infty} \delta(t) dt = 1 \quad (17)$$

# Impulse response

Since the Impulse function is zero everywhere aside from  $t = 0$ , the non-zero value of integration is a result of  $\delta(0)$ . Thus, we can say  $h(t)$  will be non-zero only if the limits of integration would include  $t = 0$ , i.e:

$$h(t) = \begin{cases} \int_{t-T}^t \delta(u) du & t - T < 0; t > 0 \\ 0 & \text{otherwise} \end{cases} \quad (18)$$

$$h(t) = \begin{cases} 1 & 0 < t < T \\ 0 & \text{otherwise} \end{cases} \quad (19)$$

## Impulse response in terms of unit step signal

The unit step signal,  $u(t)$ , is given by:

$$u(t) = \begin{cases} 1 & t \geq 0 \\ 0 & \text{otherwise} \end{cases} \quad (20)$$

On time-shifting  $u(t)$  by  $T$ , we get:

$$u(t - T) = \begin{cases} 1 & t - T \geq 0 \\ 0 & \text{otherwise} \end{cases} = \begin{cases} 1 & t \geq T \\ 0 & \text{otherwise} \end{cases} \quad (21)$$

On subtracting (20) and (21), we get our impulse response  $h(t)$  in terms of the unit step signal:

$$h(t) = u(t) - u(t - T) \quad (22)$$

# Impulse response in terms of the unit rectangular function

The unit rectangular signal,  $rect(t)$  is given by:

$$rect(t) = \begin{cases} 1 & -\frac{1}{2} \leq t \leq \frac{1}{2} \\ 0 & otherwise \end{cases} \quad (23)$$

We can obtain the impulse response  $h(t)$  in terms of  $rect(t)$  using time scaling and shifting as follows:

$$rect(Tt) = \begin{cases} 1 & -\frac{T}{2} \leq Tt \leq \frac{T}{2} \\ 0 & otherwise \end{cases} \quad (24)$$

$$rect\left(Tt + \frac{T}{2}\right) = \begin{cases} 1 & 0 \leq Tt + \frac{T}{2} \leq T \\ 0 & otherwise \end{cases} = h(t) \quad (25)$$

# Fourier Transform of impulse response

$$h(t) \xrightarrow{\mathcal{F}} H(f) \quad (26)$$

$$H(f) = \int_{-\infty}^{\infty} h(t) e^{-j2\pi ft} dt \quad (27)$$

From (19), we can write (27) as:

$$H(f) = \int_{-\infty}^0 0 dt + \int_0^T e^{-j2\pi ft} dt + \int_T^{\infty} 0 dt \quad (28)$$

$$= \frac{1 - e^{-j2\pi fT}}{j2\pi f} \quad (29)$$

$$(30)$$



## Fourier Transform of impulse response

$$= \frac{1 - \cos 2\pi fT + j \sin 2\pi fT}{j2\pi f} \quad (31)$$

$$= \frac{2 \sin^2(\pi fT) + 2j \sin(\pi fT) \cos(\pi fT)}{j2\pi f} \quad (32)$$

$$= \frac{2 \sin(\pi fT)}{2\pi f} \frac{\sin(\pi fT) + j \cos(\pi fT)}{j} \quad (33)$$

$$= Te^{-j\pi fT} \times \frac{\sin(\pi fT)}{\pi fT} \quad (34)$$

$$= Te^{-j\pi fT} \text{sinc}(\pi fT) \quad (35)$$

where  $\text{sinc}(t)$ , the sampling function is defined as:

$$\text{sinc}(t) = \begin{cases} 1 & t = 0 \\ \frac{\sin(t)}{t} & \text{otherwise} \end{cases} \quad (36)$$

# Graphs: Input and Output signals

Input signals

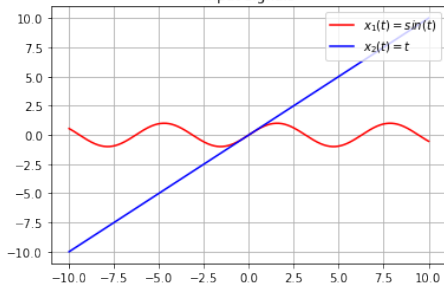


Figure:  $x_1(t) = \sin t$  and  $x_2(t) = t$

Output Signals:  $T = 1$

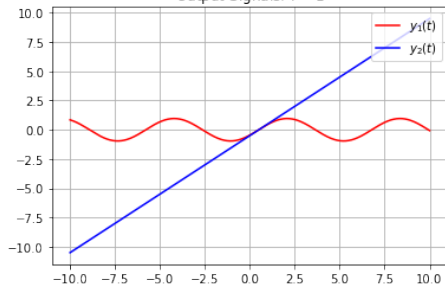


Figure:  $y_1(t)$  and  $y_2(t)$

# Graphs: Laws of Additivity and Homogeneity

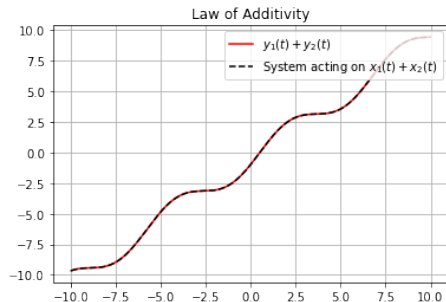


Figure: Law of Additivity

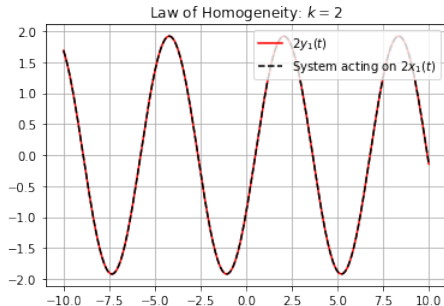


Figure: Law of Homogeneity

# Graphs: Time Invariance

