Signals & Systems

Spring 2018

Week 7

15.03.2018

Systems in SP:

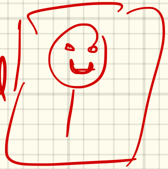
1) Filtering:

$$x[n] \longrightarrow \boxed{\begin{matrix} h \\ H \end{matrix}} \longrightarrow y[n]$$

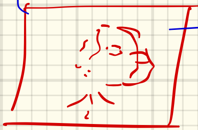
2) $x[n] \longrightarrow \boxed{H} \longrightarrow y[n] \longrightarrow \boxed{H^{-1}} \longrightarrow \tilde{x}[n]$

h

Signal



Image



Blurred Image.

need system identification (estimating H) to undo effects of the unknown system

3) Modeling physical effects:

$$x[n] \longrightarrow \boxed{H} \longrightarrow y[n]$$

Recall General form of Linear Difference eqns

$$\sum_{k=0}^{N} a_k \, y[n-k] = \sum_{k=0}^{M} b_k \, x[n-k]$$

if $a_0 = 1$, $a_k = 0$, $k=0$ $\Rightarrow y[n] = \sum_{k=0}^{M} b_k \, x[n-k]$

$$\Rightarrow y[n] = \sum \cancel{b_k}\, x(n-k) \longrightarrow \text{FIR (: Finite Impulse Response system)}$$

$$\boxed{y(n) = \sum_{k=0}^{M} h[k]\,x[n-k]}$$ convolution

Ex:

$$\sum_{k=0}^{N} a_k\, y(n-k] = \sum_{k=0}^{M-1} b_k\, x(n-k]$$

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

↳ we'll do later. IIR (Infinite Impulse Response) System.

Linearity of Systems

: satisfies the property of superposition.

Sum of Inputs $\rightarrow \boxed{H} \rightarrow$ Sum of Outputs

let

$x_1[n] \rightarrow \boxed{H} \rightarrow y_1(n)$

$x_2(n) \rightarrow \boxed{H} \rightarrow y_2(n]$

for a linear system:

$a x_1(n] + b x_2(n) \rightarrow \boxed{H} \rightarrow a y_1(n) + b y_2(n]$

Testing for a linear system:

I. $x_1(n] \rightarrow \boxed{H} \rightarrow y_1(n) \rightarrow \otimes a$; $x_2[n] \rightarrow \boxed{H} \rightarrow y_1(n) \rightarrow \otimes b$; $\oplus \rightarrow w(n)$

II. $x_1(n) \rightarrow \otimes a$; $x_2(n) \rightarrow \otimes b$; $\oplus \rightarrow a x_1(n] + b x_1(n) \rightarrow \boxed{H} \rightarrow z[n)$

$=?$

If $w(n) = z(n)$

System is linear.

Time Invariance (TI) of a System: System responds the same now as it does later.

$$x(n) \longrightarrow \boxed{H} \longrightarrow y(n)$$

$$x(n-n_0) \longrightarrow \boxed{H} \longrightarrow y(n-n_0)$$

Testing (TI):

I. $x(n) \longrightarrow \boxed{H} \longrightarrow y(n) \longrightarrow \boxed{\text{Delay } n_0} \longrightarrow y(n-n_0) = z(n)$

II. $x(n) \longrightarrow \boxed{\text{Delay } n_0} \longrightarrow x(n-n_0) \longrightarrow \boxed{H} \longrightarrow w(n)$ $\quad = ?$

n_0: integer

If $z(n) = w(n)$ then the system is time-invariant

Def: LTI (Linear & Time Invariant)

If A system is both linear & time invariant $\rightarrow$ LTI.

ex: $y(n) = (x(n))^2$: Is this an LTI? exercise:

Show that it is not linear but is time-invariant.

ex: $y[n] = x[-n]$: Is this LTI? Time-reversal System

Test TI:

I. $x(n) \longrightarrow \boxed{H} \longrightarrow y[n] = x[-n] \longrightarrow \boxed{\text{Delay } n_0} \longrightarrow x[-(n-n_0)] = x[-n+n_0]$

II. $x(n) \longrightarrow \boxed{\text{Delay } n_0} \longrightarrow y(n) = x[n-n_0] \longrightarrow \boxed{\text{System}} \longrightarrow w(n) = x[-n-n_0]$

$\neq$

Time-varying system (Not TI)

Test for linearity: I. $x_1(n) \to \boxed{H} \to y_1(n) = x_1(-n) \xrightarrow{\times a}$

$x_2(n) \to \boxed{H} \to y_2[n] = x_2(-n) \xrightarrow{\times b}$

$\oplus \to a x_1(-n) + b x_2(-n)$

II. $(a x_1(n) + b x_2(n)) \to \boxed{H} \to a x_1(-n) + b x_2(-n)$

$=$ Linear system.

Ex: $\boxed{y(n) = n\, x(n)}$: I/O relation : $q(n) \to \boxed{H} \to y(n) = n q[n]$

Test TI: I. $x(n) \to \boxed{H} \to n x(n) = y(n) \to \boxed{\text{Delay } n_0} \to w(n) = y(n-n_0)$

$= (n-n_0)\, x(n-n_0)$

II. $x(n) \to \boxed{\text{Delay } n_0} \to \boxed{q(n)} = x(n-n_0) \xrightarrow{q(n)} \boxed{H} \to y_2(n) = \underbrace{n.q(n)}_{n.x(n-n_0)}$

$\neq$

Time-varying

Test for linearity: I. $x_1(n) \to \boxed{H} \to y_1(n) = n x_1(n) \xrightarrow{\times a}$

$x_2(n) \to \boxed{H} \to y_2(n) = n x_2(n) \xrightarrow{\times b}$

$\oplus \; a n x_1(n) + b n x_2(n)$

$=$

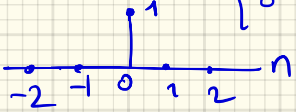
II. $\underbrace{(a x_1(n) + b x_2(n))}_{x_3(n) =} \to \boxed{H} \to n.x_3(n) = n.(a x_1(n) + b x_2(n))$

Linear System.

LTI Systems: $x(n) \rightarrow \boxed{h[n]} \rightarrow y[n]$

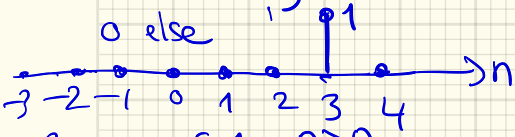
have a simple I/O relationship. Impulse Response tells us all we need to know to compute the output of the system.

Recall $\delta(n) = \begin{cases} 1 & , n=0 \\ 0 & , o/w \end{cases}$

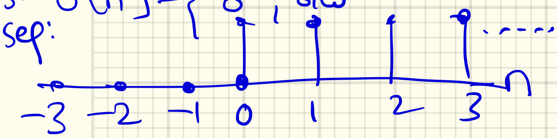


$\delta[n-3]$

0 else



step sep: $u(n) = \begin{cases} 1 & , n \geq 0 \\ 0 & , o/w \end{cases}$



Impulse Response

Set $\underline{x[n] = \delta[n]}$ $\rightarrow \boxed{H} \rightarrow h[n] \triangleq$ Impulse Response fn. (sep.)

Input = Impulse sep

$y(n) = h(n)$

We know $h[n]$ When $x(n)$ is the input

$x(n) \rightarrow \boxed{H} \rightarrow y[n] = h[n] * x(n)$

LTI System

convolution operator

$$y[n] \triangleq \sum_{k=-\infty}^{\infty} \underbrace{h[k]}_{bk} \, x[n-k]$$

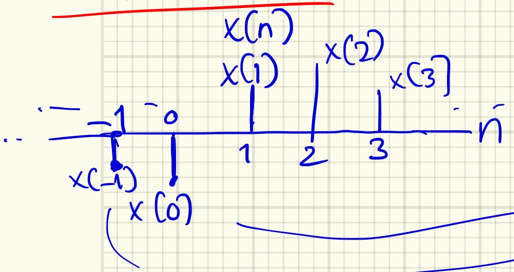
let $l = n-k$

change of variables

$$y(n) = \sum_{l=-\infty}^{\infty} x[l] \, h[n-l]$$

LTI System:

$$h(n) * x(n) = \sum h[k]\,x(n-k)$$



$$x[n] = \ldots + x[-1]\,\delta[n+1] + x[0]\,\delta[n] + x(1)\,\delta(n-1) + x(2)\,\delta(n-2) + \ldots$$

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

LTI System:

$$x(n) \rightarrow \boxed{T} \rightarrow y[n] = T\{x(n)\} = T\Big\{\underbrace{\sum_{k=-\infty}^{\infty} x[k]\,\delta[n-k]}\Big\}$$

linearity

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

$$= \sum x[k]\,\underbrace{T\{\delta[n-k]\}}$$

time invariance

impulse response

$$\delta[n] \rightarrow \boxed{T} \rightarrow h[n]$$

$$\delta[n-k] \rightarrow \boxed{T} \rightarrow h[n-k]$$

due to Time Inv.

$$y(n) = \sum_{k=-\infty}^{\infty} x[k]\,h[n-k]$$

We showed: for an LTI system w/ impulse response $h(n)$, the I/O relation is given by the convolution btw input and $h(n)$.

$$y(n) = x(n) * h(n) \quad \text{convolution.}$$

Properties of Convolution Operator $*$

Show these / Prove as exercise

(1) Commutative : $x_1(n) * x_2(n) = x_2(n) * x_1(n)$

(2) Associative : $\left(x_1[n] * x_2(n]\right) * x_3(n) = x_1[n] * \left(x_2[n] * x_3[n]\right)$

(3) Distributive over Addition : $h[n] * \left(x_1[n] + x_2[n]\right)$

$$= h[n] * x_1[n] + h[n] * x_2[n]$$

(4) Identity Element : $\delta[n]$: unit impulse seq.

$$x[n] * \delta[n] = \sum_{k=-\infty}^{\infty} x[k] \underbrace{\delta[n-k]}_{= \begin{cases} 1, & k=n \\ 0, & o/w \end{cases}} = x[n]$$

(5) $\delta[n-n_0] * x[n] = x(n-n_0)$

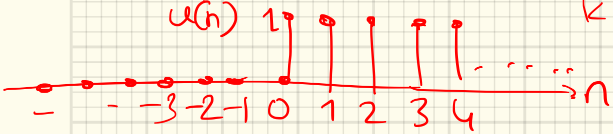
$$\delta[n-1] * x[n] = \sum_{k=-\infty}^{\infty} x(k)\, \delta[(n-1)-k] = x[n-1]$$

Recall

$x(n) \rightarrow$ $\boxed{\text{Delay System } n_0}$ $\rightarrow y(n) = x[n-n_0]$: Compute the impulse response ? of the delay system.

Set $x(n) = \delta[n] \rightarrow$ $\boxed{\text{"}}$ $\rightarrow h(n) = \delta[n-n_0]$:

STEP sequence (fn.): $u(n) = \sum_{k=0}^{\infty} \delta[\underbrace{n-k}_{\triangleq \ell}] = \begin{cases} 1, & n \geq 0 \\ 0, & n < 0 \end{cases}$

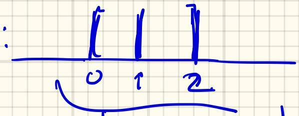


$\hookrightarrow u[n] = \sum_{\ell=-\infty}^{n} \delta[\ell] = \delta[n] + \delta[n-1] + \delta[n-2] + \delta[n-3] + \dots$

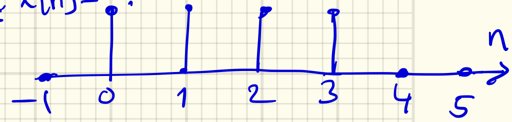
Step Response of a LTI System

$x(n) = u[n] \longrightarrow \boxed{\text{LTI}} \longrightarrow s[n]$

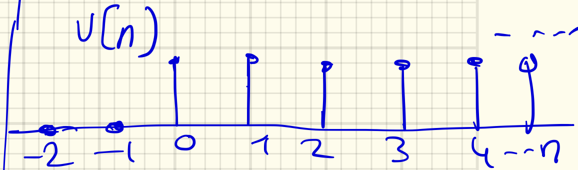
$\underbrace{x(n) = u[n] - u[n-3]}$: creates a window fn. of length 3.

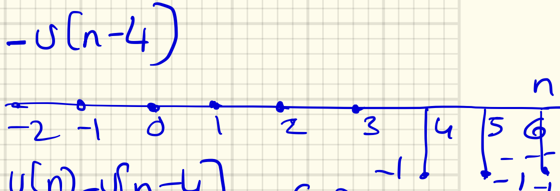


ex: $x[n] = ?$



Use 2 step fn's to represent this signal.

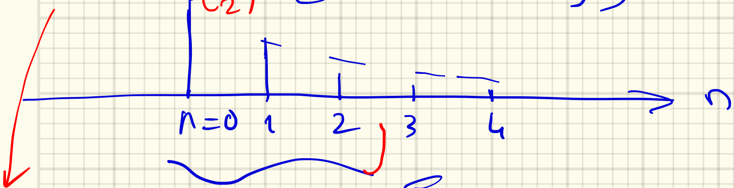




$u[n] - u[n-4] = x(n)$

ex: $x(n) = \underbrace{\left(\frac{1}{2}\right)^n}_{\text{exponential seq.}} \cdot \underline{u(n)}$

or $= \left(\frac{1}{2}\right)^n \cdot \left[u(n) - u[n-3]\right]$



pointwise multiplication.

windowed signal

Step Response of an LTI System

$$u(n) = \sum_{k=0}^{\infty} \delta(n-k) \longrightarrow \boxed{\text{LTI}} \longrightarrow s(n)$$

$$\|$$

$$x(n) \longrightarrow \boxed{\text{LTI}} \longrightarrow y(n) = h(n) * x(n)$$

$h[n]$ ← impulse response : $\delta[n) \longrightarrow \boxed{\text{LTI}} \longrightarrow h(n)$

$$y(n) = h(n) * u(n) = h(n) * \left(\sum_{k=0}^{\infty} \delta(n-k]\right)$$

distributive over addition

$$s(n) = \sum_{k=0}^{\infty} \left(h(n] * \delta[n-k]\right)$$

$$s(n) = \sum_{k=0}^{\infty} h[n-k]$$; Given h (impulse resp) → going to s(n) (step response)

ex: Given step response → $h(n) = ?$

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

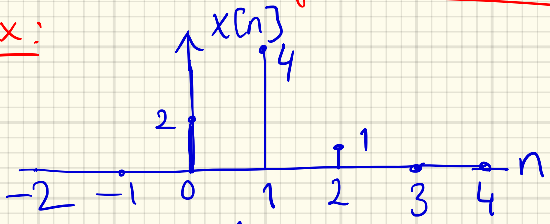
$$u[n] \longrightarrow \boxed{\text{LTI}} \longrightarrow s[n)$$

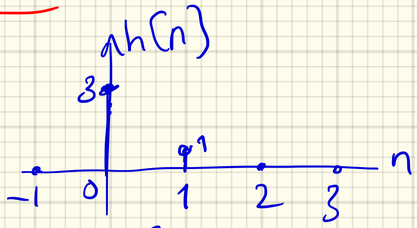
$$u[n-1) \longrightarrow \boxed{\text{LTI}} \longrightarrow s[n-1]$$

$$= \delta[n] \longrightarrow \boxed{\text{LTI}} \longrightarrow h(n) = s[n] - s(n-1]$$

Computation of Convolution: Given $x[n]$ & $h(n)$, Compute $y[n]=?$

Ex:





$$y[n] = \sum_{k=0}^{1} h[k]\, x[n-k]$$

1 way

n=0

$$y[0] = \sum_{k=0}^{1} h(k)\, x[-k]$$

$$y[1] = \sum_{k=0}^{1} h(k)\, x[1-k]$$

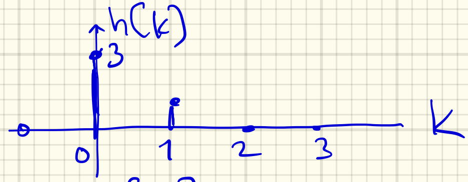
$$y[2] = \sum h(k)\, x[2-k]$$

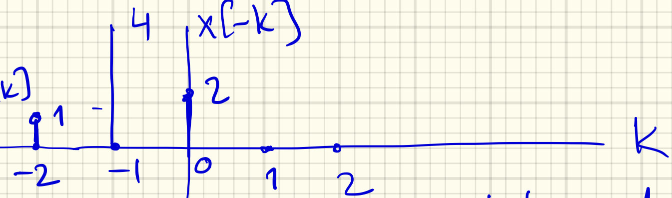
$$y[3] = \sum h[k]\, x[3-k]$$

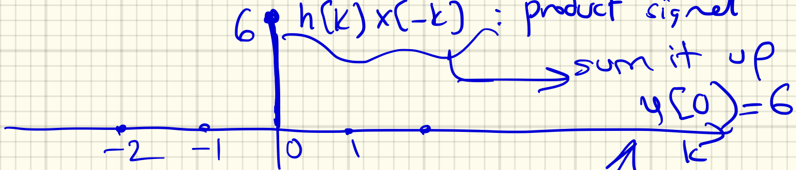
$n=0$

① use $h(k)$ as it is,

② flip & shift $x(k)$

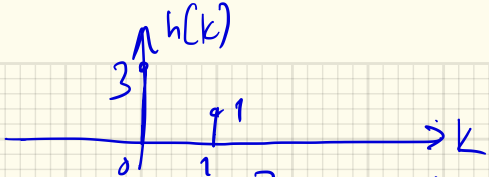


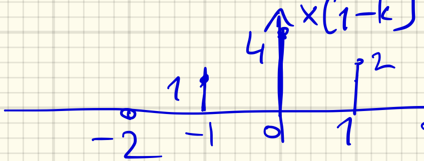




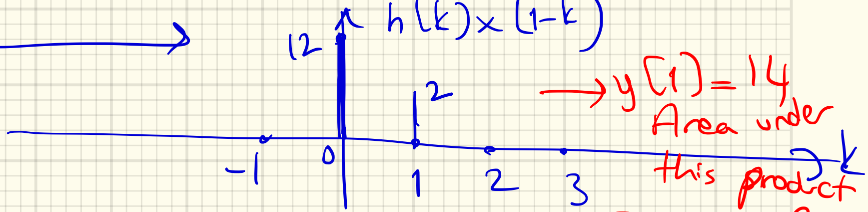
$n=0$

$n=1 \rightarrow y(1) = \sum_{k=0}^{1} h[k]\,x[1-k]$





: shifted $x[-k]$ to the right by 1.

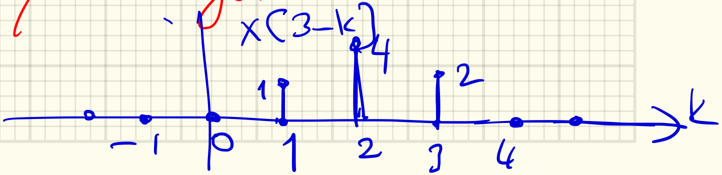


$\rightarrow y[1]=14$ Area under this product signal.

Exercise: calculate these at home: $y(2)$, $y(3)$ ← non-zero values

$y[-1]$, $y[4]$ ← check.

This is Graphical convoln method / Works for CT convolution.



Another Way: $y(n) = \sum_{k=0}^{1} h(k)x[n-k] = h[0]x[n] + h[1]x[n-1]$

Table Method

n	0	1	2	3	4	5
$x(n)$	2	4	1	0	0	0
$h(n)$	3	1	0	0	0	0
$h(0)x(n)$	6	12	3	0	0	0
+ $h(1)x(n-1)$	0	2	4	1	0	0
$y(n)$	6	14	7	1	0	0

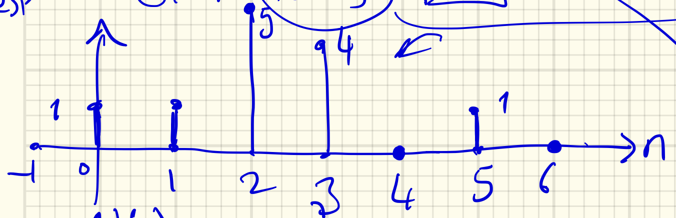
only valid for DT convol.

Ex: FIR Filter: $y[n] = x[n] - x[n-1]$: First order Difference filter

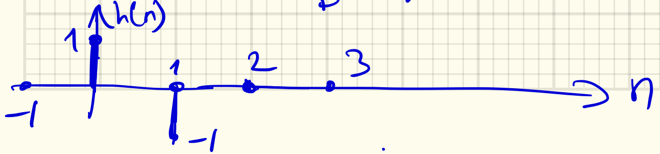
$h[n] = \delta[n] - \delta[n-1]$ impulse response

Given $x[n] \rightarrow \boxed{FIR} \rightarrow y(n) = ?$

$x[n] = \delta[n] + \delta[n-1] + 5\delta[n-2] + 4\delta[n-3] + \delta[n-5]$



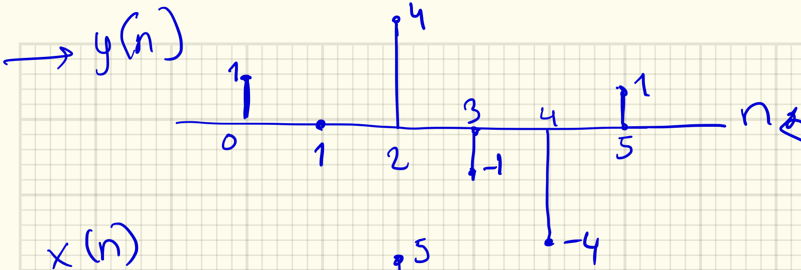
h(n)



$y[n] = h(n) * x[n]$

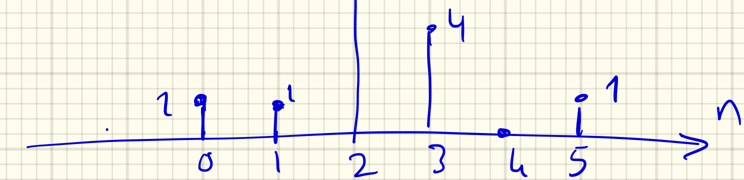
$= \delta[n] + \delta[n-1] + 5\delta[n-2] + 4\delta[n-3] + \delta[n-5]$

$- (\delta[n-1] + \delta[n-2] + 5\delta[n-3] + 4\delta[n-4] + \delta[n-6])$



$h(n) = \delta(n) - \delta[n-1]$

derivative $\equiv$ difference filter



smoothing filter.

eg. if we had 5pt-RAF : exercise do this

$$y(n) = \sum_{k=0}^{4} \frac{1}{5} x(n-k)$$