Notes for ECE 30100 - Signals and Systems

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Course Description

Classification, analysis and design of systems in both the time- and frequency-domains. Continuous-time linear systems: Fourier Series, Fourier Transform, bilateral Laplace Transform. Discrete-time linear systems: difference equations, Discrete-Time Fourier Transform, bilateral z-Transform. Sampling, quantization, and discrete-time processing of continuous-time signals. Discrete-time nonlinear systems: median-type filters, threshold decomposition. System design examples such as the compact disc player and AM radio.

Introduction

As this course studies signals and systems, it behooves us to understand what signals and systems are. A signal is a quantity that varies over time. Examples include voltage waveform on a circuit, height as a function of age, or pulses of light through fiber optic.

We distinguish between continuous time (CT) and discrete time (DT) signals. CT signals have a continuous independent variable, such as time. DT signals have a discrete independent variable, such as the date. The indices are a set of integers.

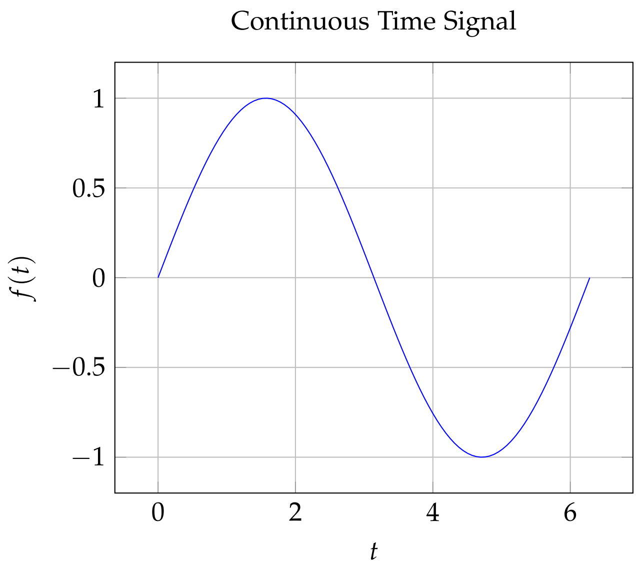


Figure 1: Continuous Time Signal

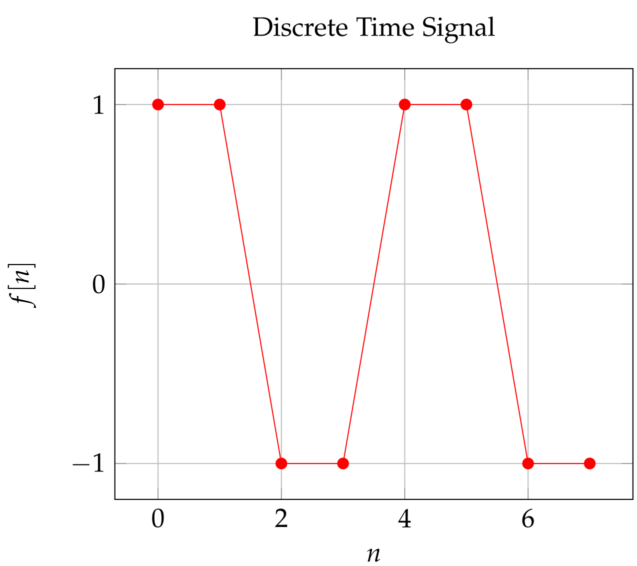


Figure 2: Discrete Time Signal

In the most general terms, a systems transform inputs to outputs. They're interconnections of subsystems. Examples of systems include, topically, circuits.

Similarly to signals, there are continuous time systems and discrete time systems. In a CT system, the input and output are continuous. Conversely, DT systems have discrete inputs and outputs.

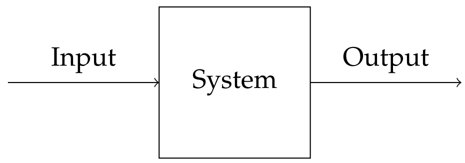


Figure 3: System Diagram

The astute reader will notice systems operate much like functions. We use function notation to describe systems. For a CT system, we write $y(t) = S(x(t))$ with parentheses to show it's CT. For DT, we use brackets like $y[t] = S(x[t])$.

It's easy to imagine a system with continuous input and discrete output, or vice versa. These are called samplers and reconstructors respectively. We'll mostly be looking at linear time-invariant discrete systems, since they have the greatest application to ECE.

Linearity

Readers are familiar with the concept of linearity, which mathematically may be expressed as

$$f(a+b) = f(a) + f(b) \tag{1}$$

Linear systems possess the property of superposition, so given an input as a sum of weighted inputs the output is a sum of weighted outputs.

The necessary and sufficient conditions for linearity in a CT system are if the input is $\alpha_1 x_1(t) + \alpha_2 x_2(t)$ the output is $S(\alpha_1 x_1(t)) + S(\alpha_2 x_2(t))$. Formally,

$$S(\alpha_1 x_1(t) + \alpha_2 x_2(t)) = \alpha_1 S(x_1(t)) + \alpha_2 S(x_2(t)). \tag{2}$$

Likewise for DT systems,

$$S[\alpha_1 x_1[t] + \alpha_2 x_2[t]] = \alpha_1 S[x_1[t]] + \alpha_2 S[x_2[t]]. \tag{3}$$

This equality for hold for any real valued α_1 and α_2.

Consider the CT system S given by $y(t) = tx(t)$. We are interested in determining if the system is linear. We test it with the definition of linearity,

$$\begin{aligned} y(\alpha_1 x_1(t) + \alpha_2 x_2(t)) &= t(\alpha_1 x_1(t) + \alpha_2 x_2(t)) && (4) \\ &= t\alpha_1 x_1(t) + t\alpha_2 x_2(t) && (5) \\ &= \alpha_1 y(x_1(t)) + \alpha_2 y(x_2(t)) && (6) \end{aligned}$$

Since this is the definition of linearity, the system is linear.

Why do we care? We care because linearity gives us many useful properties and makes solving systems much easier. If we know the output for any set of inputs, we can find the output for any linear combination of those inputs.

Classifying Signal Types

Before we proceed we must be able to classify signal types. We have so far seen continuous time and discrete time signals, and now we introduce *complex* signals as well. Let's define all of these here:

- DT: $x[n]$ is a sequence of complex values, including purely real values. numbers. Example: $x[n] = \frac{n}{2}$.
- CT: $x(t)$ is complex (including purely real) and continuous for all real values of t. Example: $x(t) = \frac{t}{2} - jt$.
- Complex:

For DT, complex $x[n]$ can be represented in Cartesian or polar form. For Cartesian,

$$x[n] = x_{Re}[n] + jx_{Im}[n]. \tag{7}$$

For polar,

$$x[n] = A[n]e^{j\Theta[n]}. \tag{8}$$

We can swap between the two with Euler's formula.

$$A[n]e^{j\Theta[n]} = A[n]\cos(\Theta[n]) + jA[n]\sin(\Theta[n]) \tag{9}$$

$$x_{Re}[n] + jx_{Im}[n] = \sqrt{x_{Re}[n]^2 + x_{Im}[n]^2} \times e^{j\arctan(\frac{x_{Im}[n]}{x_{Re}[n]})} \tag{10}$$

DT vs. CT is one option to classify signals. Another possibility is Energy vs. Power. For this class, energy in a continuous time system is the area under the squared magnitude of the signal. Mathematically energy over (t_1, t_2) is equal to

$$E = \int_{t_1}^{t_2} |x(t)|^2 dt \tag{11}$$

$$= \int_{t_1}^{t_2} (x_{Re}(t)^2 + x_{Im}(t)^2) dt. \tag{12}$$

For DT systems, the formula for energy is

$$E = \sum_{n=n_1}^{n_2} |x[n]|^2 \tag{13}$$

$$= \sum_{n=n_1}^{n_2} (x_{Re}[n]^2 + x_{Im}[n]^2). \tag{14}$$

The total energy E_∞ is the energy from $t = -\infty$ to $t = \infty$.

Power is energy per unit time, or in terms of calculus $P(t) = \frac{d}{dt}E(t)$. For CT, average power is

$$P_{avg} = \frac{1}{t_2 - t_1} \int_{t_1}^{t_2} |x(t)|^2 dt. \tag{15}$$

For DT,

$$P_{avg} = \frac{1}{n_2 - n_1 + 1} \sum_{n=n_1}^{n_2} |x[n]|^2. \tag{16}$$

The overall average power is

$$P_\infty = \lim_{T \to \infty} \frac{1}{2T} \int_{-T}^{T} |x(t)|^2 dt \tag{17}$$

for CT and

$$P_\infty = \lim_{N \to \infty} \frac{1}{2N+1} \sum_{n=-N}^{N} |x[n]|^2 \tag{18}$$

for DT time.

Transformations

Just as with functions, signals can be transformed in time. Here are the different transformations that can be applied to signals.

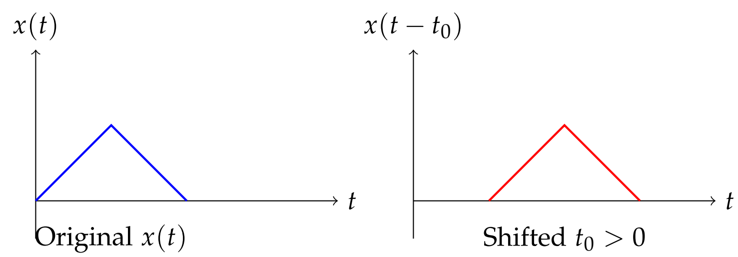
Time Shift

A CT time shift is given by $x(t) \to x(t - t_0)$, where t_0 is real.

- $t_0 > 0$: shifted to the right or delayed by t_0
- $t_0 < 0$: shifted to the left or advanced by t_0

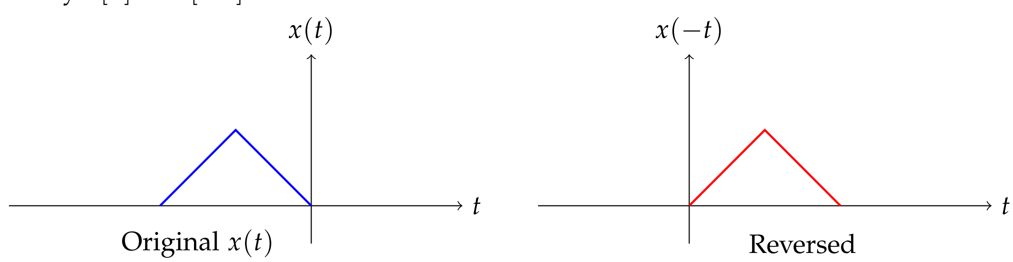
A DT time shift is given by $x[n] \to x[n - n_0]$, where n_0 is an integer.

- $n_0 > 0$: shifted to the right or delayed by n_0
- $n_0 < 0$: shifted to the left or advanced by n_0



Time Reversal

A CT time reversal is given by $x(t) \to x(-t)$. A DT time reversal is given by $x[n] \to x[-n]$.



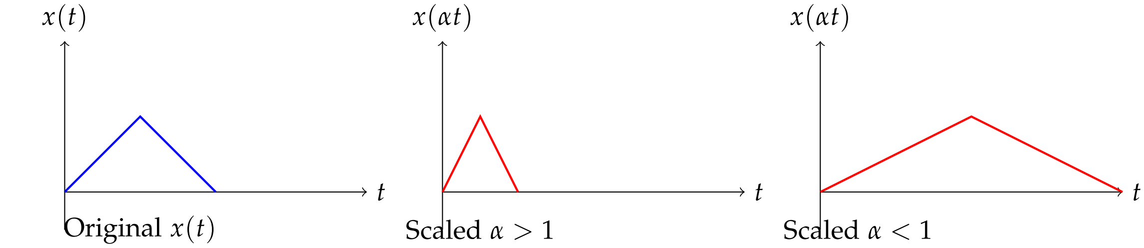
Time Scaling

A CT time scaling is given by $x(t) \to x(\alpha t)$, where $\alpha > 0$ is the time scaling factor.

If $\alpha < 0$, that's viewed as a combination of reversal and scaling.

- $\alpha > 1$: shorter timescale, or sped up
- $\alpha < 1$: longer timescale, or slowed down

A DT time scaling is given by $x[n] \to x[\alpha n]$.



A signal is even if it's symmetric with respect to the dependent axis. Mathematically, if $x(t) = x(-t)$.

A signal is odd if it's symmetric with respect to the origin. Mathematically, if $x(-t) = -x(t)$.

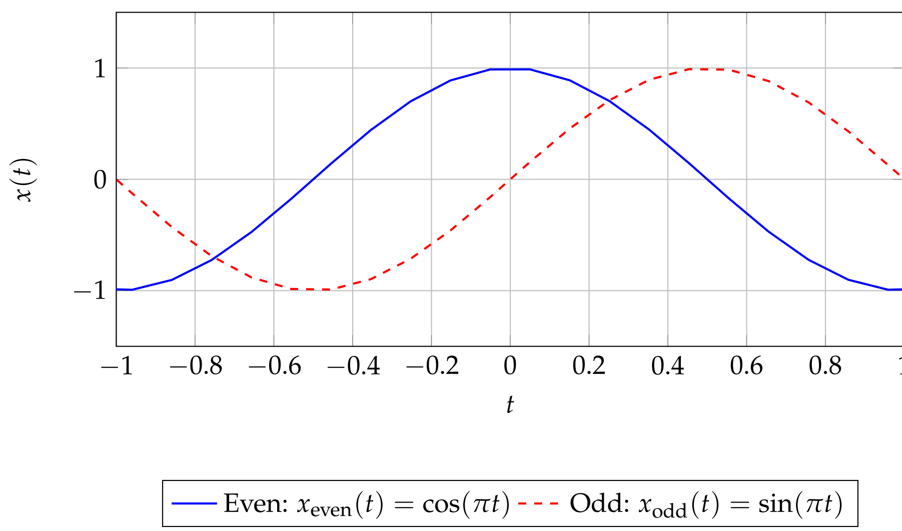


Figure 4: Even and odd signals

Signals can be odd, even, both, or neither. $x(t) = 0$, for instance, is both even and odd. $x + 1$ is neither.

The product of two odd signals is even (e.g. $x \times x^3$). The product of two evens is even ($x^2 \times 2$). The product of an odd and an even is odd ($x \times x^2$).

Any signal can be written as the sum of an even and an odd signal using these formulas:

$$
\begin{aligned}
x(t) &= x_{even}(t) + x_{odd}(t) && (19)\\
&= \frac{x(t) + x(-t)}{2} + \frac{x(t) - x(-t)}{2} && (20)\\
& && (21)
\end{aligned}
$$

$$
\begin{aligned}
x[n] &= x_{even}[n] + x_{odd}[n] && (22)\\
&= \frac{x[n] + x[-n]}{2} + \frac{x[n] - x[-n]}{2} && (23)\\
& && (24)
\end{aligned}
$$

Periodicity

A system is periodic if $x(t) = x(t+T)$, or in the case of discrete time, if $x[n] = x[n+N]$.

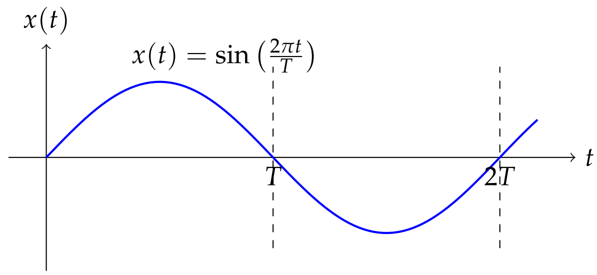


Figure 5: Periodic CT Signal

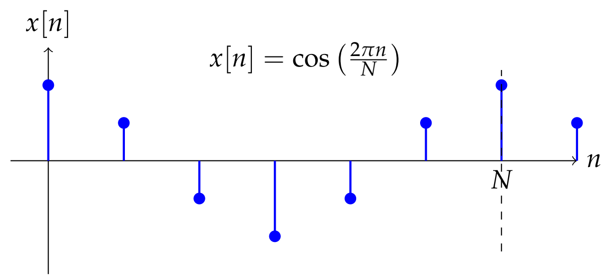


Figure 6: Periodic DT Signal

The fundemental period is the smallest T_0 (or N_0) such that $x(t) = x(t+T_0)$ (or $x[n] = x[n+N_0]$). If $x(t)$ is periodic, $x_{Re}(t) + jx_{Im}(t)$ is also periodic. However, if $x_1(t)$ and $x_2(t)$ are periodic then it is not necessarily the case that $x_1(t) + x_2(t)$ is periodic. Consider $x_1(t) = \sin(t)$ and $x_2(t) = \sin(\sqrt{2}t)$. $x_1(t) + x_2(t) = \sin(t) + \sin(\sqrt{2}t)$. $x_1(t)$ has period 2π. $x_2(t)$ has period $\frac{2\pi}{\sqrt{2}}$. However, their sum is not periodic and in fact the sum of any $x_1(t)$, $x_2(t)$ will be aperiodic when the ratio of their periods is irrational.

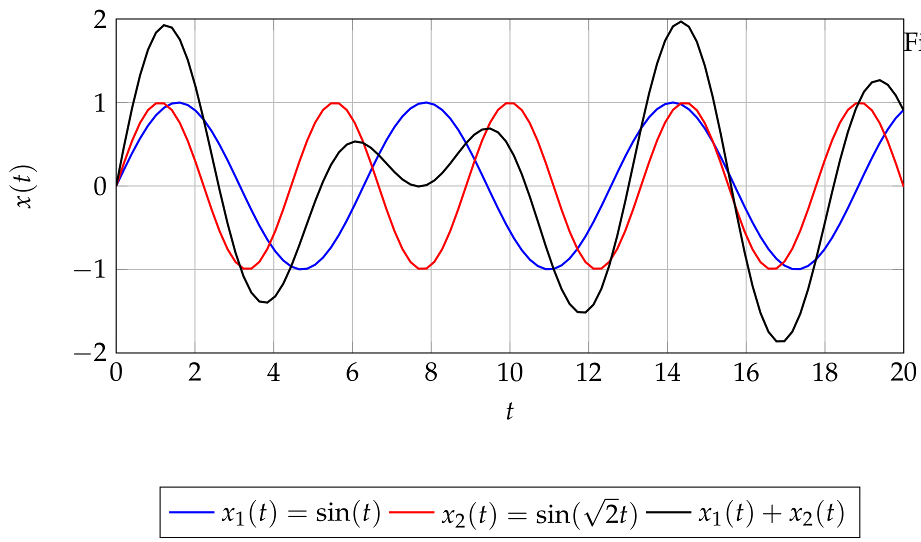


Figure 7: Periodic Signals Sum

Reference

- $E = mc^2$