

- 2.14 (p.171)
- 2.16
- Additional problem

2.14 $h(t) = u(t) - u(t-1)$

(a) Input = $x(t)$. Is output $y(t) = \int_{t-1}^t x(\gamma) d\gamma$?

Find output w/ convolution. Use t -folded version since h is simpler.

$$y(t) = \int_{-\infty}^{\infty} x(\gamma) h(t-\gamma) d\gamma \rightarrow h=0 \text{ almost everywhere, except } \begin{matrix} 0 < t-\gamma < 1 \\ -t < -\gamma < 1-t \\ t > \gamma > t-1 \end{matrix} \quad \begin{matrix} 0, 1 \text{ are limits from } h(\cdot) \end{matrix}$$

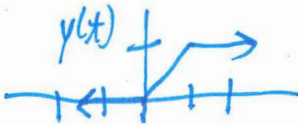
$$= \int_{t-1}^t x(\gamma) d\gamma$$

Q.E.D.

(b) $x(t) = u(t)$

$$y(t) = \begin{cases} 0, & t < 0 \text{ (no overlap)} \\ t, & 0 < t < 1 \text{ (partial overlap of } h \text{ w/ } t, \text{ or evaluate: } \int_0^t 1 d\gamma = t \\ 1, & t > 1 \text{ (} \int_{t-1}^t 1 d\gamma = 1 \end{cases}$$

$t-1 < 0 \Rightarrow x(t-1) = 0$, so omit



(c) Step response is output when input is unit step, so we solved in (b).

$$s(t) = \begin{cases} 0, & t < 0 \\ t, & 0 < t < 1 \\ 1, & t > 1 \end{cases} = u(t) - u(t-1) = t u(t) - (t-1) u(t-1)$$

System is LTI (since $h(t)$ exists) \therefore linear, so $\int \cdot \frac{d}{dt}$ commute w/ system.

Let input be derivative of original input:

$$y(t) = \int \left(\frac{d}{dt} x(\gamma) \right) h(t-\gamma) d\gamma = \frac{d}{dt} \left(\int x(\gamma) h(t-\gamma) d\gamma \right) = \frac{d}{dt} (s(t))$$

Let $x(t) = u(t)$, then $\frac{d}{dt} x(t) = \delta(t)$, then $y(t) = h(t) = \frac{d}{dt} s(t)$

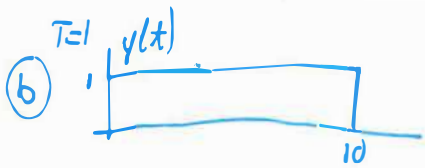
\therefore The impulse response, $h(t)$, is the derivative of the step response $s(t)$.

2.16 $h(t) = u(t) - u(t-1)$ $x(t) = \sum_{k=0}^9 \delta(t - kT)$ limits of integration

a) $y(t) = \int x(\gamma) h(t-\gamma) d\gamma = \int \sum_k \delta(\gamma - kT) (h(t-\gamma) - h(t-\gamma-1)) d\gamma$ if $T=1$

$= \sum_k \int_{t-1}^t \delta(\gamma - kT) \cdot 1 d\gamma = \sum_k (u(t - \uparrow - kT) - u(t - \uparrow - kT)) \stackrel{\downarrow}{=} u(0) - u(10)$

↑ value of $h(\cdot)$ given γ
↑ general solution
↑ add up 1×1 pulses starting @ 0, 1, ..., 9.



c) $T=0.5$. The pulses now overlap.

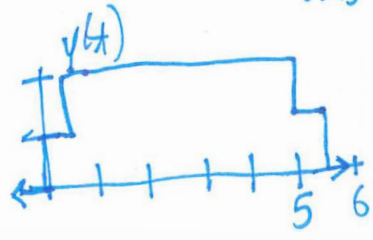
One approach: all even k : 0, 2, 4, 6, 8 $\rightarrow y_1(t) = u(t) - u(t-5)$

↓ start @ $kT=0$
↓ start @ $kT=4$

all odd k : 1, 3, 5, 7, 9 $\rightarrow y_2(t) = u(t-0.5) - u(t-5.5)$

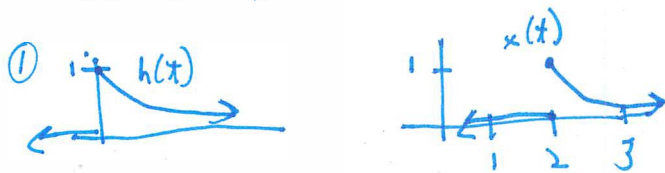
↓ start @ $kT = \frac{1}{2}$
↓ start @ $kT = 4\frac{1}{2}$

$y(t) = y_1(t) + y_2(t) = \cancel{u(t)} + \cancel{u(t-0.5)} - \cancel{u(t-5)} - \cancel{u(t-5.5)}$
 $= u(t) + u(t-0.5) - u(t-5) - u(t-5.5)$



Additional Problem

$$h(t) = e^{-t} u(t) \quad x(t) = e^{-(2(t-2))} u(t-2)$$



$$\textcircled{2} \quad y(t) = \int x(\gamma) h(t-\gamma) d\gamma = \int_{-\infty}^{\infty} e^{-2(\gamma-2)} u(\gamma-2) e^{-(t-\gamma)} u(t-\gamma) d\gamma$$

Graphically, from ①, we see after folding $h(\cdot)$ that there is no overlap until it is shifted right by $t=2$. The overlap, then, for all $t \geq 2$, occurs from $\gamma=2$ to t .

$$y(t) = \begin{cases} 0, & t < 2 \\ \int_2^t e^{-2(\gamma-2)} e^{-(t-\gamma)} d\gamma = y_1(t), & t \geq 2 \end{cases}$$

$$y_1(t) = \int_2^t e^{-2\gamma+4-t+\gamma} d\gamma = \int_2^t e^{4-t-\gamma} d\gamma = \left[e^{4-t-\gamma} \right]_{\gamma=2}^{\gamma=t}$$

$$= \left[0 - e^{4-t-2} \right] = e^{4-t-2} = e^{2-t}$$

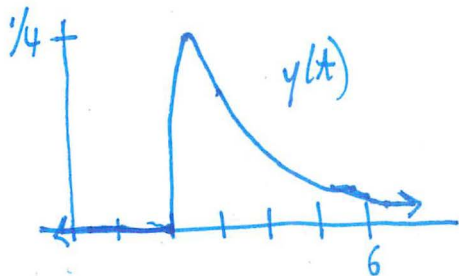
use limit

$$= - \left(e^{4-2t} - e^{4-t-2} \right) = e^{2-t} - e^{2(2-t)}$$

Check: If $t=2^+$, $y_1(t) = e^{2-2} - e^{2(2-2)} = 1-1=0$
 If $t=2^-$, $y(t) = 0$ $\Rightarrow \therefore y(t)$ is 0th order continuous, as it must be since no δ s are involved

$$\text{So, } y(t) = \begin{cases} 0, & t < 2 \\ e^{2-t} - e^{2(2-t)}, & t \geq 2 \end{cases}$$

(3)

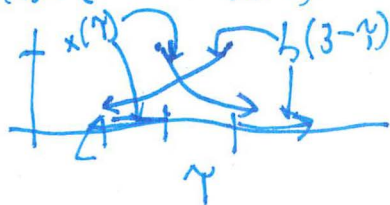


(4)

vs. τ , $t=3$

$$x(\tau) = e^{-(2(\tau-2))} u(\tau-2)$$

$$h(t-\tau) = e^{-(t-\tau)} u(t-\tau) = e^{-(3-\tau)} u(3-\tau)$$



The product of $x(\tau)$ & $h(3-\tau)$ is 0 unless $2 < \tau < 3$.

$y(3) =$ area under product from $-\infty$ to ∞ ,
 which = area under product from 2 to 3.