

- 1.23. We want to find the smallest N_0 such that $m(2\pi/N)N_0 = 2\pi k$ or $N_0 = 2\pi k/m$, where k is an integer. If N_0 has to be an integer, then N must be a multiple of m/k and m/k must be an integer. This implies that m/k is a divisor of both m and N . Also, if we want the smallest possible N_0 , then m/k should be the GCD of m and N . Therefore, $N_0 = N/\gcd(m, N)$.

- 1.24. (a) If $x(t)$ is periodic $x(t+NT) = x(t)$, where $\omega_0 = 2\pi/N$. This implies that

$$\frac{2\pi}{NT} NT = 2\pi k \quad \Rightarrow \quad \frac{T}{N} = \frac{k}{N} = \text{a rational number.}$$

- (b) If $T/N = p/q$ then $x(t) = x(t + p/qT)$. The fundamental period is $q/\gcd(p, q)$ and the fundamental frequency is

$$\frac{2\pi}{q/\gcd(p, q)} = \frac{2\pi p}{p} \gcd(p, q) = \frac{2\pi}{p} \gcd(p, q) = \frac{2\pi q}{p} \gcd(p, q).$$

- (c) $p/\gcd(p, q)$ periods of $x(t)$ are needed.

- 1.27. (a) From the definition of $\delta_{xy}(t)$, we have

$$\begin{aligned} \delta_{xy}(t) &= \int_{-\infty}^{\infty} x(t) + y(t) \delta(t) dt \\ &= \int_{-\infty}^{\infty} x(t) \delta(t) dt + \int_{-\infty}^{\infty} y(t) \delta(t) dt \\ &= \delta_x(t) + \delta_y(t). \end{aligned}$$

- (b) Since from part (a) that $\delta_{xy}(t) = \delta_{yx}(t)$. This implies that $\delta_{xy}(t)$ is even. Therefore, the odd part of $\delta_{xy}(t)$ is zero.

- (c) Here, $\delta_{xy}(t) = \delta_{yx}(t) - T$ and $\delta_{xy}(t) = \delta_{yx}(t)$.

- 1.28. (a) We know that $\delta_{xx}(t) = \delta_{xx}(t)$. Therefore,

$$\lim_{T \rightarrow 0} \delta_{xx}(t) = \lim_{T \rightarrow 0} \frac{1}{T} \delta_{xx}(t).$$

This implies that

$$\delta(t) = \frac{1}{T} \delta(t).$$

- (b) The plots are as shown in Figure S1.28.

- 1.29. We have

$$\lim_{T \rightarrow 0} \omega_0 \delta(t) = \lim_{T \rightarrow 0} \omega_0 T \delta(t) = \delta.$$

Also,

$$\lim_{T \rightarrow 0} \omega_0 T \delta(t) = \frac{1}{T} \delta(t).$$

or

- 1.31. (a) $y(t) = 2x(t)$. Therefore, the system is time-invariant.

- (b) $y(t) = (2n - 1)x(t)$. This is not time-invariant because $y(t) \neq N_2 y(t - 1)$ or $N_2 y(t) = N_2(2n - 1)x(t)$.

- (c) $y(t) = x(t)(1 + (-1)^t + (-1)^{t+1}) = 2x(t)$. Therefore, the system is time-invariant.

- 1.32. (a) Consider two systems S_1 and S_2 connected in series. Assume that if $x_1(t)$ and $x_2(t)$ are the inputs to S_1 , then $y_1(t)$ and $y_2(t)$ are the outputs, respectively. Also, assume that if $y_1(t)$ and $y_2(t)$ are the inputs to S_2 , then $r_1(t)$ and $r_2(t)$ are the outputs, respectively. Since S_2 is linear, we may write

$$r_1(t) = ay_1(t) + bz_1(t) \quad \text{and} \quad r_2(t) = ay_2(t) + bz_2(t),$$

where a and b are constants. Since S_2 is also linear, we may write

$$r_1(t) + r_2(t) \xrightarrow{S_2} r_1(t) + r_2(t).$$

We may therefore conclude that

$$ay_1(t) + ay_2(t) \xrightarrow{S_2} r_1(t) + r_2(t) = r_1(t) + r_2(t).$$

Therefore, the series combination of S_1 and S_2 is linear.

Since S_1 is time-invariant, we may write

$$y_1(t - T_0) \xrightarrow{S_1} y_1(t - T_0)$$

and

$$y_2(t - T_0) \xrightarrow{S_2} y_2(t - T_0).$$

Therefore,

$$y_1(t - T_0) \xrightarrow{S_1} y_1(t - T_0).$$

Therefore, the series combination of S_1 and S_2 is time-invariant.

- (b) False. Let $y(t) = x(t) + 1$ and $x(t) = y(t) - 1$. These correspond to two realizable systems. If these systems are connected in series, then $x(t) = x(t)$ which is a linear system.

- (c) Let us name the output of system 1 as $w(t)$ and the output of system 2 as $v(t)$. Then,

$$\begin{aligned} y(t) &= x(t) + w(t) = x(t) + \frac{1}{2}x(t) + 1 = \frac{3}{2}x(t) + 1 \\ &= x(t) + \frac{1}{2}x(t) + 1 = \frac{3}{2}x(t) + 1. \end{aligned}$$

The overall system is linear and time-invariant.

- 1.42. (a) We have

$$x(t) \xrightarrow{S} y(t).$$

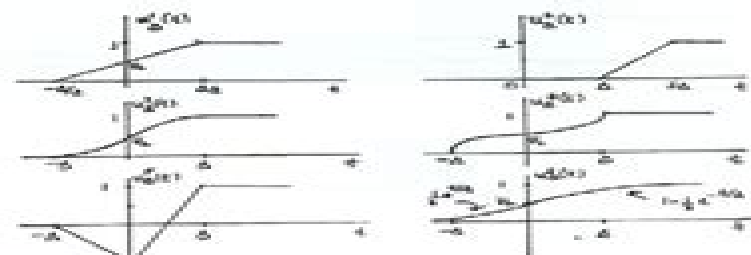


Figure S1.28

We have

$$y(t) = \int_{-\infty}^{\infty} x(t) \delta(t) dt = \int_{-\infty}^{\infty} x(t) \delta(t) dt = x(t).$$

Therefore,

$$y(t) = \begin{cases} x(t) & \text{if } t < 0 \\ x(t) & \text{if } t > 0 \\ x(t) & \text{for } t = 0 \end{cases} \quad \text{and} \quad y(t) = x(t) + x(t) = 2x(t) \quad \text{for } t = 0.$$

- 1.43. (a) If a system is additive, then

$$0 = x(t) + x(t) \rightarrow y(t) = y(t) + y(t) = 0.$$

Also, if a system is homogeneous, then

$$0 = 0x(t) \rightarrow y(t) = 0.$$

- (b) $y(t) = x^2(t)$ is not a system.

- (c) No. For example, consider $y(t) = \int_{-\infty}^{\infty} x(\tau) d\tau$ with $x(t) = x(t) - x(t) = 0$. Then $x(t) = 0$ for $t > 1$, but $y(t) = 1$ for $t > 1$.

or

Since S is time-invariant,

$$x(t - T) \xrightarrow{S} y(t - T).$$

Now, if $x(t)$ is periodic with period T , $x(t) = x(t - T)$. Therefore, we may conclude that $y(t) = y(t - T)$. This implies that $y(t)$ is also periodic with period T . A similar argument may be made in discrete time.

(b)

- 1.44. (a) Assumption: If $x(t) = 0$ for $t < t_0$, then $y(t) = 0$ for $t < t_0$. To prove that: The system is causal.

Let us consider an arbitrary signal $x_1(t)$. Let us consider another signal $x_2(t)$ which is the same as $x_1(t)$ for $t < t_0$ but for $t > t_0$, $x_2(t) \neq x_1(t)$. Since the system is linear,

$$x_1(t) - x_2(t) \xrightarrow{S} y_1(t) - y_2(t).$$

Since $x_1(t) = x_2(t) = 0$ for $t < t_0$, by our assumption $y_1(t) = y_2(t) = 0$ for $t < t_0$. This implies that $y_1(t) = y_2(t)$ for $t < t_0$. In other words, the output is not affected by input values for $t < t_0$. Therefore, the system is causal.

Assumption: The system is causal. To prove that: If $x(t) = 0$ for $t < t_0$, then $y(t) = 0$ for $t < t_0$.

Let us assume that the signal $x(t) = 0$ for $t < t_0$. Then, we may express $x(t)$ as $x(t) = x_1(t) - x_2(t)$, where $x_1(t) = x_2(t)$ for $t < t_0$. Since the system is linear, the output to $x(t)$ will be $y(t) = y_1(t) - y_2(t)$. Now, since the system is causal, $y_1(t) = y_2(t)$ for $t < t_0$ implies that $y(t) = 0$ for $t < t_0$. Therefore, $y(t) = 0$ for $t < t_0$.

- (b) Consider $y(t) = x(t) + 1$. Now, $x(t) = 0$ for $t < t_0$ implies that $y(t) = 1$ for $t < t_0$. Since the system is nonlinear and non-causal.

- (c) Consider $y(t) = x(t) + 1$. This system is nonlinear and causal. This does not satisfy the condition of part (a).

- (d) Assumption: The system is invertible. To prove that: $y(t) = 0$ for all t only if $x(t) = 0$ for all t .

Consider

$$x(t) = 0 \rightarrow y(t) = 0.$$

Since the system is linear,

$$2x(t) = 0 \rightarrow 2y(t) = 0.$$

Since the input has not changed in the two above equations, we require that $y(t) = 2y(t)$. This implies that $y(t) = 0$. Since we have assumed that the system is invertible, only one input could have led to this particular output. That input must be $x(t) = 0$.

Assumption: $y(t) = 0$ for all t if $x(t) = 0$ for all t . To prove that: The system is invertible.

Suppose that

$$x_1(t) \rightarrow y(t) = 0$$

and

$$x_2(t) \rightarrow y(t) = 0.$$

or

or

or

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