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~~Introduction to Frequency Domain Representation Of Signals~~ Convolution Sum - Problems

Part 1 Laplace Transforms and Convolution

Frequency Response An Introduction to Filters

Graphical convolution example

Continuous-Time Convolution 1

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Solution: $A_1=3$, $t_1=0$, $A_2=-3$, $t_2=1$ or -1 $x(t)$ is $dt t dx$ (is Because - ==- k k t t g) $2 (d, dt t dx)$
 $(=3g(t)-3g(t-1))$ or $dt t dx$ $(=3g(t)-3g(t+1))$ 1.15. Consider a system S with input $x[n]$ and output $y[n]$. This system is obtained through a series interconnection of a system S_1 followed by a system S_2 .

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These lecture notes were prepared using mainly our textbook titled "Signals and Systems" by Alan V. Oppenheim, Alan S. Willsky and S. Hamid Nawab, but also from handwritten notes of Fatih Kamisli and A. Ozgur Yilmaz. Most gures and tables in the notes are also taken from the textbook. This is the rst version of the notes.

Lecture Notes EE301 Signals and Systems I

6.003 covers the fundamentals of signal and system analysis, focusing on representations of discrete-time and continuous-time signals (singularity functions, complex exponentials and geometrics, Fourier representations, Laplace and Z transforms, sampling) and representations of linear, time-invariant systems (difference and differential equations, block diagrams, system functions, poles and ...

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Discrete-time processing of continuous-time signals : 19: Discrete-time sampling : 20: The Laplace transform : 21: Continuous-time second-order systems : 22: The z-transform : 23:

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Mapping continuous-time filters to discrete-time filters : 24: Butterworth filters : 25: Feedback : 26

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