6.003: Signal Processing

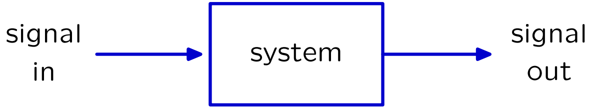
Frequency Response and Filtering

- Discrete-Time Frequency Response
- Continuous-Time Frequency Response

October 14, 2021

Context: The System Abstraction

Describe a **system** (physical, mathematical, or computational) by the way it transforms an **input signal** into an **output signal**.



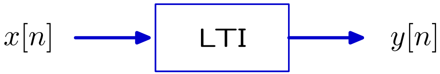
This abstraction is particularly powerful for **linear and time-invariant** systems, which are both **prevalent** and **mathematically tractable**.

Three important representations for LTI systems:

- **Difference/Differential Eq:** algebraic input/output **constraint** $\surd$
- Convolution: represent system by unit-sample/impulse response $\surd$
- Filter: represent a system by its frequency response

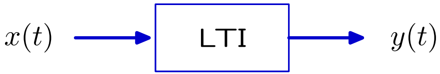
Representing Systems with Difference/Differential Equations

Discrete-time systems that can be described by linear **difference** equations with constant coefficients are linear and time-invariant.



$$\sum_l c_l y[n-l] = \sum_m d_m x[n-m]$$

Continuous-time systems that can be described by linear **differential** equations with constant coefficients are linear and time-invariant.



$$\sum_l c_l \frac{d^l y(t)}{dt^l} = \sum_m d_m \frac{d^m x(t)}{dt^m}$$

– natural and compact representations of many systems

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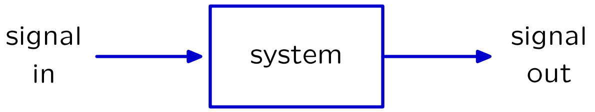

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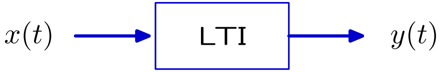
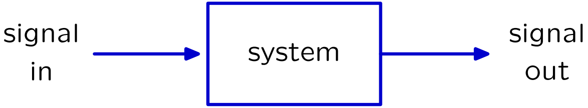
Unit-Sample Response and Impulse Response

Discrete-time systems that are linear and time-invariant can be completely specified by their response to a **unit-sample signal**.



If $\delta[n] \rightarrow h[n]$, then $x[n] \rightarrow y[n] = (x * h)[n] = \sum_m x[m]h[n-m]$

Continuous-time systems that are linear and time-invariant are completely specified by their response to a unit **impulse** function.



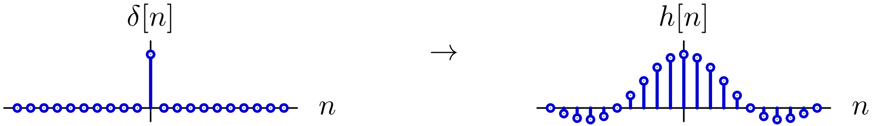
If $\delta(t) \rightarrow h(t)$, then $x(t) \rightarrow y(t) = (x * h)(t) = \int x(\tau)h(t-\tau)d\tau$

– an LTI system is completely characterized by **a single signal**

Unit-Sample Response

The unit-sample response is a **complete** description of a system.

This is a bit surprising since $\delta[n]$ is such a **simple signal.**
The unit-sample signal is the **shortest** possible non-trivial DT signal!

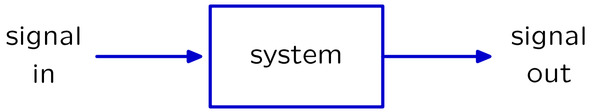


The response to this simple signal determines the response to **any** other input signal:

$$x[n] \rightarrow y[n] = (x * h)[n] = \sum_m x[m]h[n-m]$$

Context: The System Abstraction

Describe a **system** (physical, mathematical, or computational) by the way it transforms an **input signal** into an **output signal**.



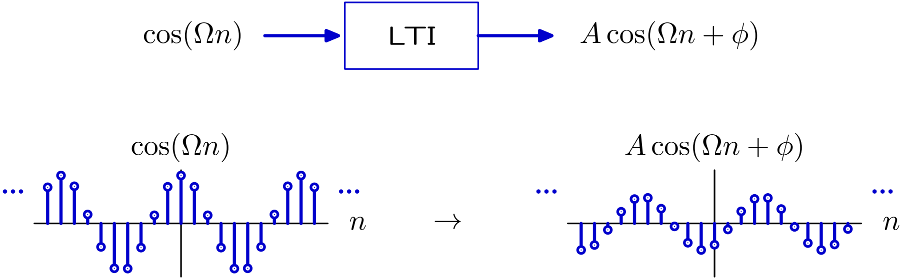
This abstraction is particularly powerful for **linear and time-invariant** systems, which are both **prevalent** and **mathematically tractable**.

Three important representations for LTI systems:

- **Difference/Differential Eq:** algebraic input/output **constraint** $\surd$
- **Convolution:** represent system by **unit-sample/impulse response** $\surd$
- **Filter:** represent a system by its **frequency response**

Frequency Response

The **frequency response** is a third way to characterize a linear time-invariant system. This characterization is based on responses to **sinusoids.**



The idea is to characterize a system by the way A and ϕ vary with Ω.

Sinusoids differ from the unit-sample signal in important ways:

- **eternal** (longest possible signals) versus **transient** (shortest possible)
- comprises a **single** frequency versus a **sum** of all possible frequencies

Frequency Response

Using complex exponentials to characterize the frequency response.

Notice that the complex valued A can represent both amplitude and phase.
We can find A using convolution.

$$y[n] = (x * h)[n] = \sum_{m=-\infty}^{\infty} x[n-m]h[m] = \sum_{m=-\infty}^{\infty} e^{j\Omega(n-m)}h[m]$$

$$= e^{j\Omega n} \sum_{m=-\infty}^{\infty} h[m]e^{-j\Omega m} = H(\Omega)\, e^{j\Omega n}$$

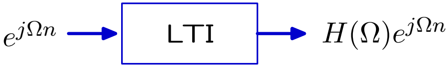
The response to a complex exponential is a complex exponential with the **same frequency** but possibly **different amplitude and phase.**

The map for how a system modifies the amplitude and phase of a complex exponential input is the **Fourier transform of the unit-sample response.**

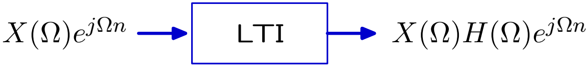
Frequency Response

The frequency response is a **complete** characterization of an LTI system.

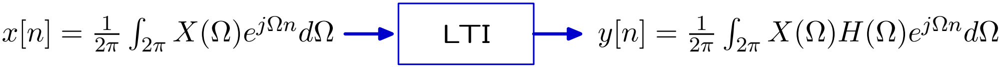
1. One can always find the frequency response of a system.



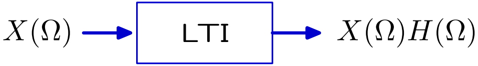
2. Scaling the input by a constant scales the output by the same constant.



3. Linearity implies that the response to a sum is the sum of the responses.



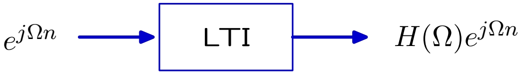
4. The Fourier transform of the output is $X(\Omega)H(\Omega)$.



The transform of the output is $H(\Omega)$ times the transform of the input.

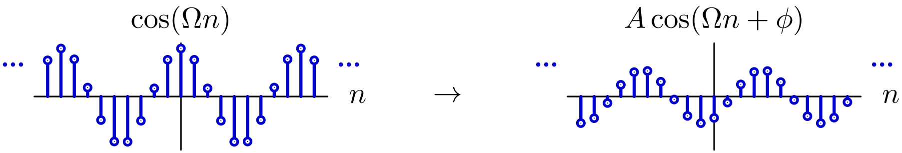
Frequency Response

The frequency response is a **complete** description of a system.



This is a bit surprising since $e^{j\Omega n}$ contains a **single** frequency.

$\rightarrow$ can find the output of a system by breaking the input into its constituent frequencies and summing the responses to each frequency – one-at-a-time.



The frequency response can be used to find response to **any** input signal:

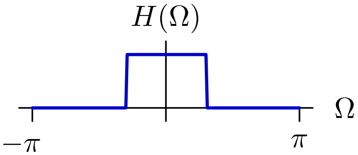
$$X(\Omega) \rightarrow Y(\Omega) = H(\Omega)X(\Omega)$$

Frequency Response

The frequency response can be an **insightful** description of a system.

Example:

A low-pass filter passes frequencies near 0 and rejects those near π.

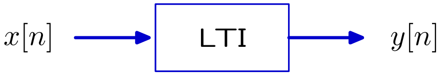


Very natural way to describe audio components:

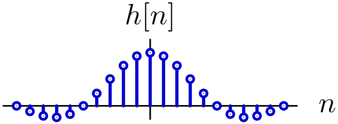
- microphones
- loudspeakers
- audio equalizers

Unit-Sample Response and Frequency Response

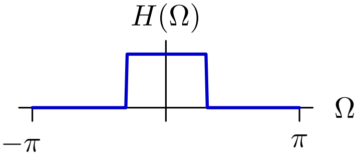
Two complete representations for linear, time-invariant systems.



Unit-Sample Response: responses across time for a unit-sample input.



Frequency Response: responses across frequencies for sinusoidal inputs.



The **frequency response** is Fourier transform of **unit-sample response**!

Example

Find the frequency response of a system described by the following:

$$y[n] - \alpha y[n-1] = x[n]$$

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$$y[n] - \alpha y[n-1] = x[n]$$

Method 1:

Find the unit-sample response and take its Fourier transform.

$$h[n] - \alpha h[n-1] = \delta[n]$$

Solve the difference equation for $h[n]$.

$$h[n] = \delta[n] + \alpha h[n-1]$$

First order $\rightarrow$ need one initial condition: $h[-1] = 0$

$$\begin{aligned} h[0] &= \delta[0] + \alpha h[-1] = 1 \\ h[1] &= \delta[1] + \alpha h[0] = \alpha \\ h[2] &= \delta[2] + \alpha h[1] = \alpha^2 \\ h[3] &= \delta[3] + \alpha h[2] = \alpha^3 \end{aligned}$$

$$h[n] = \alpha^n u[n]$$

$$H(\Omega) = \sum_{n=-\infty}^{\infty} h[n] e^{-j\Omega n} = \sum_{n=0}^{\infty} \alpha^n e^{-j\Omega n} = \sum_{n=0}^{\infty} \left(\alpha e^{-j\Omega}\right)^n = \frac{1}{1-\alpha e^{-j\Omega}}$$

Example

Find the frequency response of a system described by the following:

$$y[n] - \alpha y[n-1] = x[n]$$

Method 2:

Find the response to $e^{j\Omega n}$ directly.

$$x[n] = e^{j\Omega n}$$

Because the system is linear and time-invariant, the output will have the same frequency as the input, but possibly different amplitude and phase.

$$y[n] = H(\Omega)e^{j\Omega n}$$

$$y[n-1] = H(\Omega)e^{j\Omega(n-1)} = H(\Omega)e^{-j\Omega}e^{j\Omega n}$$

Substitute into the difference equation.

$$H(\Omega)e^{j\Omega n} - \alpha H(\Omega)e^{-j\Omega}e^{j\Omega n} = H(\Omega)(1-\alpha e^{-j\Omega})e^{j\Omega n} = e^{j\Omega n}$$

Since $e^{j\Omega n}$ is never 0, we can divide it out.

$$H(\Omega) = \frac{1}{1 - \alpha e^{-j\Omega}}$$

Same answer as method 1.

Example

Find the frequency response of a system described by the following:

$$y[n] - \alpha y[n-1] = x[n]$$

Method 3:

Take the Fourier transform of the difference equation.

$$Y(\Omega) - \alpha e^{-j\Omega} Y(\Omega) = X(\Omega)$$

Solve for $Y(\Omega)$.

$$Y(\Omega) = \frac{1}{1 - \alpha e^{-j\Omega}} X(\Omega)$$

Since $Y(\Omega) = H(\Omega)X(\Omega)$,

$$H(\Omega) = \frac{1}{1 - \alpha e^{-j\Omega}}$$

Same answer as methods 1 and 2.

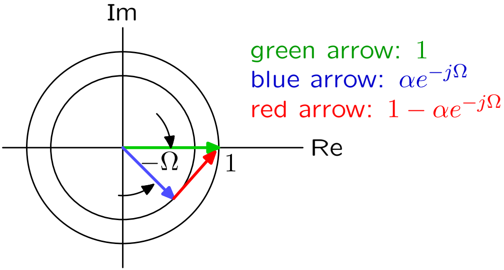
Example

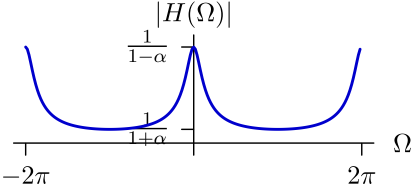
Plot the frequency response.

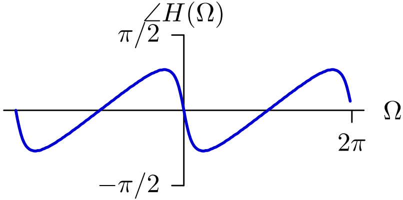
$$H(\Omega) = \frac{1}{1-\alpha e^{-j\Omega}}$$

Note that denominator is the difference of 2 complex numbers.

If $0 < \alpha < 1$:





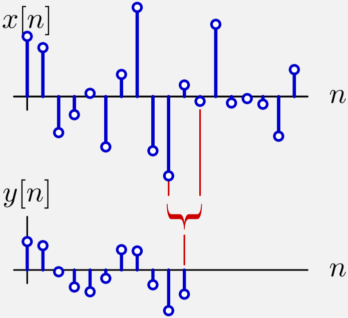


Amplifies at low frequencies and attenuates high frequencies. Adds delay.

Check Yourself

Find the frequency response of a three-point averager:

$$y[n] = \frac{1}{3}\Big(x[n-1] + x[n] + x[n+1]\Big)$$



The System Abstraction

The system abstraction applies equally well for continuous-time signals.

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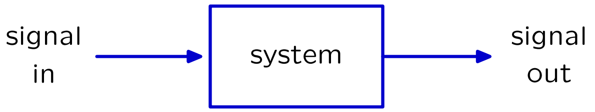


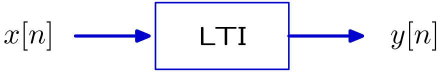
This abstraction is particularly powerful for **linear and time-invariant** systems, which are both **prevalent** and **mathematically tractable**.

Three important representations for LTI systems:

- **Differential Equation:** algebraic **constraint** on **derivatives** √
- **Convolution:** represent a system by its **impulse response** √
- **Filter:** represent a system by its **frequency response**

Representing Systems with Difference/Differential Equations

Discrete-time systems that can be described by linear **difference** equations with constant coefficients are linear and time-invariant.



$$\sum_{l} c_l y[n-l] = \sum_{m} d_m x[n-m]$$

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– natural and compact representations of many systems

Unit-Sample Response and Impulse Response

Discrete-time systems that are linear and time-invariant can be completely specified by their response to a **unit-sample signal**.

$$\text{If } \delta[n] \to h[n], \text{ then } x[n] \to y[n] = (x * h)[n] = \sum_m x[m]h[n-m]$$

Continuous-time systems that are linear and time-invariant are completely specified by their response to a unit **impulse** function.

$$\text{If } \delta(t) \to h(t), \text{ then } x(t) \to y(t) = (x * h)(t) = \int x(\tau)h(t-\tau)d\tau$$

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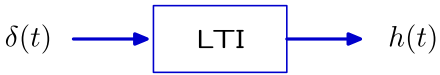
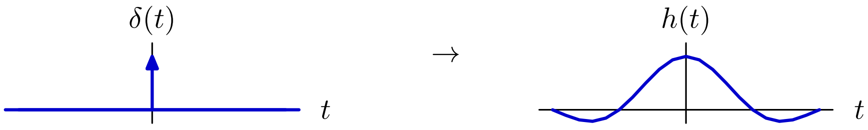
Impulse Response

The impulse response is a **complete** description of a system.



This is a bit surprising since $\delta(t)$ is zero almost everywhere.

The impulse function is the **shortest** possible non-trivial CT signal!

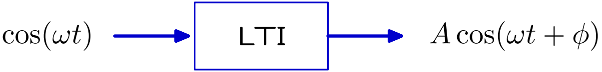


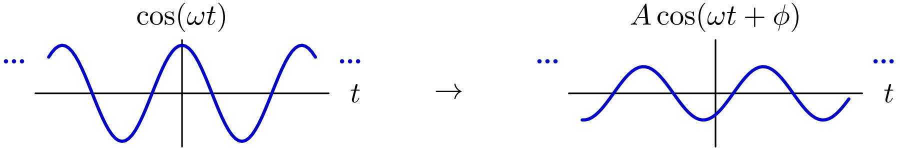
The response to this signal determines the response to **any** other input.

$$x(t) \rightarrow y(t) = (x * h)(t) = \int x(\tau)h(t-\tau)d\tau$$

Frequency Response

The **frequency response** is a third way to characterize a linear time-invariant system. This characterization is based on responses to **sinusoids.**





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Frequency Response

Using complex exponentials to characterize the frequency response.

Notice that the complex valued A can represent both amplitude and phase. We can find A using convolution.

$$y(t) = (x * h)(t) = \int_{-\infty}^{\infty} x(t-\tau)h(\tau)d\tau = \int_{-\infty}^{\infty} e^{j\omega(t-\tau)}h(\tau)d\tau$$

$$= e^{j\omega t}\int_{-\infty}^{\infty} h(\tau)e^{-j\omega\tau}d\tau = H(\omega)\, e^{j\omega t}$$

The response to a complex exponential is a complex exponential with the **same frequency** but possibly **different amplitude and phase.**

The map for how a system modifies the amplitude and phase of a complex exponential input is the **Fourier transform of the impulse response.**

Frequency Response

The frequency response is a **complete** characterization of an LTI system.

1. One can always find the frequency response of a system.

$$e^{j\omega t} \longrightarrow \boxed{\text{system}} \longrightarrow H(\omega)e^{j\omega t}$$

2. Scaling the input by a constant scales the output by the same constant.

$$X(\omega)e^{j\omega t} \longrightarrow \boxed{\text{system}} \longrightarrow X(\omega)H(\omega)e^{j\omega t}$$

3. Linearity implies that the response to a sum is the sum of the responses.

$$\frac{1}{2\pi}\int_{-\infty}^{\infty} X(\omega)e^{j\omega t}d\omega \longrightarrow \boxed{\text{system}} \longrightarrow \frac{1}{2\pi}\int_{-\infty}^{\infty} X(\omega)H(\omega)e^{j\omega t}d\omega$$

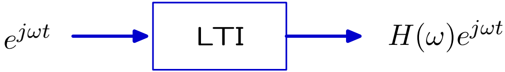
4. The Fourier transform of the output is $X(\omega)H(\omega)$.

$$X(\omega) \longrightarrow \boxed{\text{system}} \longrightarrow X(\omega)H(\omega)$$

The transform of the output is $H(\omega)$ times the transform of the input.

Frequency Response

The frequency response is a **complete** description of a system.



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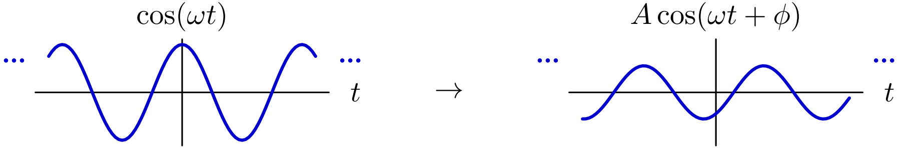


The frequency response can be used to find response to **any** input signal:

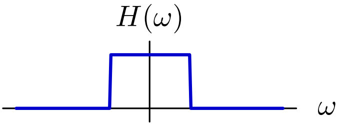
$$X(\omega) \rightarrow Y(\omega) = H(\omega)X(\omega)$$

Frequency Response

The frequency response can be an **insightful** description of a system.

Example:

A low-pass filter passes frequencies near 0 and rejects those far from 0.

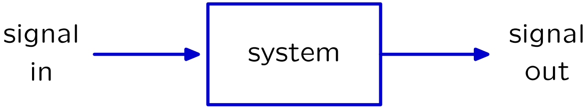


Very natural way to describe audio enhancements:

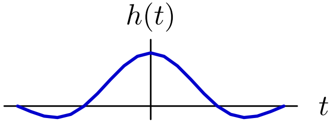
- microphones
- loudspeakers
- audio equalizers

System Abstraction

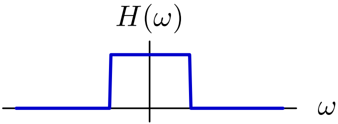
Two complete representations for linear, time-invariant systems.



Impulse Response: responses across time for a inpulse input.



Frequency Response: responses across frequencies for sinusoidal inputs.



The **frequency response** is Fourier transform of **impulse response**!

Example

Find the frequency response of a system described by the following:

$$y(t) + \alpha \frac{dy(t)}{dt} = x(t)$$

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Method 1:

Find the response to $e^{j\omega t}$ directly.

$$x(t) = e^{j\omega t}$$

Because the system is linear and time-invariant, the output will have the same frequency as the input, but possibly different amplitude and phase.

$$y(t) = H(\omega)e^{j\omega t}$$

$$\frac{dy(t)}{dt} = j\omega H(\omega)e^{j\omega t}$$

Substitute into the differential equation.

$$H(\omega)e^{j\omega t} + j\omega\alpha H(\omega)e^{j\omega t} = (1 + j\omega\alpha)H(\omega)e^{j\omega t} = e^{j\omega t}$$

Since $e^{j\omega t}$ is never 0, we can divide it out.

$$H(\omega) = \frac{1}{1 + j\omega\alpha}$$

Example

Find the frequency response of a system described by the following:

$$y(t) + \alpha \frac{dy(t)}{dt} = x(t)$$

Method 2:

Take the Fourier transform of the differential equation.

$$Y(\omega) + j\omega\alpha Y(\omega) = X(\omega)$$

Solve for $Y(\omega)$.

$$Y(\omega) = \frac{1}{1 + j\omega\alpha} X(\omega)$$

Since $Y(\omega) = H(\omega)X(\omega)$,

$$H(\omega) = \frac{1}{1 + j\omega\alpha}$$

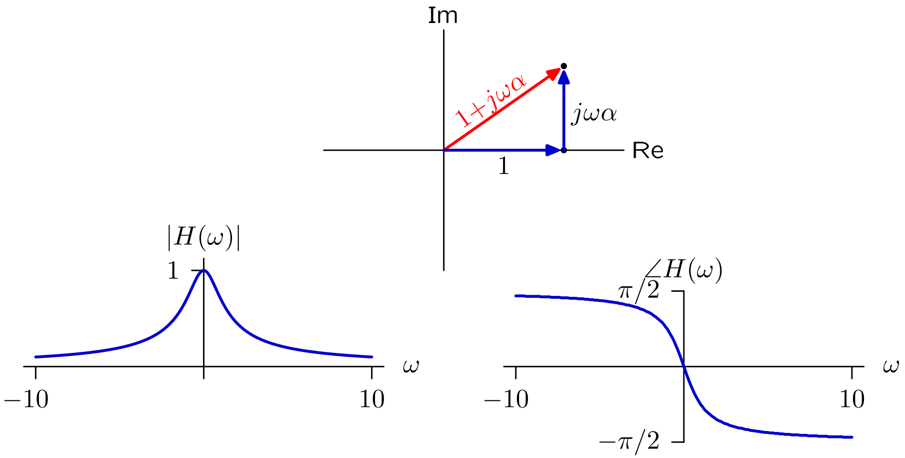
Same answer as method 1.

Example

Plot the frequency response.

$$H(\omega) = \frac{1}{1 + j\omega\alpha}$$

Note that denominator is sum of 2 complex numbers.



Amplifies low frequencies, attenuates high frequencies, adds phase delay.

Check Yourself

Find the frequency response of a rectangular box filter:

$$y(t) = \frac{1}{2}\int_{t-1}^{t+1} x(\tau)d\tau$$

(This CT filter is analogous to the three-point averager in DT.)

Summary

The Fourier transform of the response of a DT LTI system is the product of the Fourier transform of the input times the system's **frequency response.**

$$Y(\Omega) = H(\Omega)X(\Omega)$$

The frequency response $H(\Omega)$ is the Fourier transform of the unit-sample response $h[n]$.

The Fourier transform of the response of a CT LTI system is the product of the Fourier transform of the input times the system's **frequency response.**

$$Y(\omega) = H(\omega)X(\omega)$$

The frequency response $H(\omega)$ is the Fourier transform of the impulse response $h(t)$.