

ESE 531: Digital Signal Processing

Lec 12: February 22, 2018

Frequency Response of LTI Systems



Lecture Outline

- ❑ Frequency Response of LTI Systems
 - Magnitude Response
 - Simple Filters
 - Phase Response
 - Group Delay
 - Example: Zero on Real Axis



Frequency Response of LTI System

- LTI Systems are uniquely determined by their impulse response

$$y[n] = \sum_{k=-\infty}^{\infty} x[k] h[n-k] = x[k] * h[k]$$

- We can write the input-output relation also in the z-domain

$$Y(z) = H(z)X(z)$$

- Or we can define an LTI system with its frequency response

$$Y(e^{j\omega}) = H(e^{j\omega})X(e^{j\omega})$$

- $H(e^{j\omega})$ defines magnitude and phase change at each frequency



Frequency Response of LTI System

$$Y(e^{j\omega}) = H(e^{j\omega})X(e^{j\omega})$$

- We can define a magnitude response

$$|Y(e^{j\omega})| = |H(e^{j\omega})| |X(e^{j\omega})|$$

- And a phase response

$$\angle Y(e^{j\omega}) = \angle H(e^{j\omega}) + \angle X(e^{j\omega})$$



Phase Response

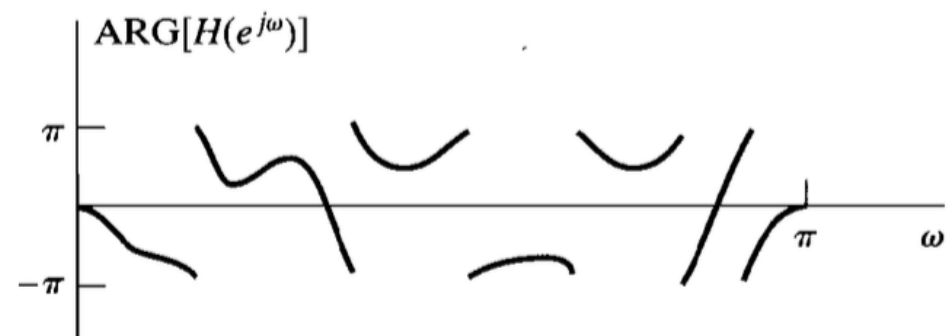
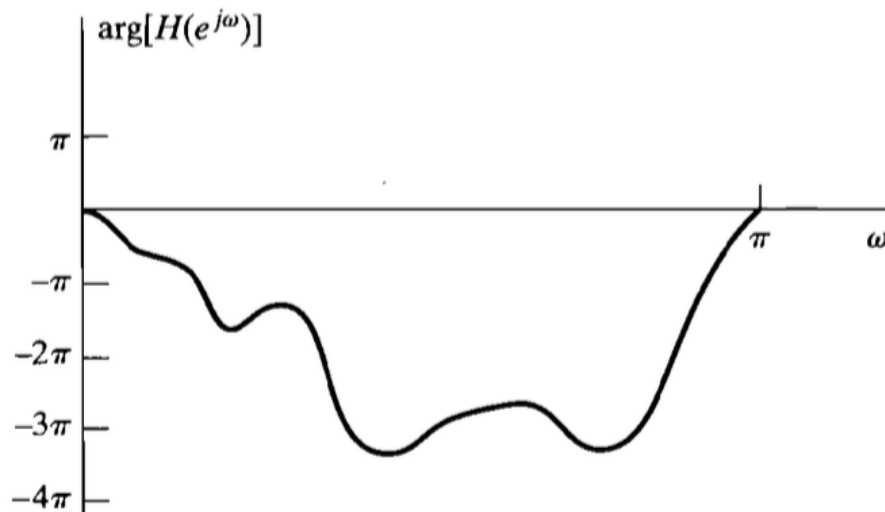
- Limit the range of the phase response

$$-\pi < \text{ARG}[H(e^{j\omega})] \leq \pi.$$

Phase Response

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Group Delay

- General phase response at a given frequency can be characterized with group delay, which is related to phase

$$\text{grd}[H(e^{j\omega})] = -\frac{d}{d\omega} \{\arg[H(e^{j\omega})]\}$$

- More later...



Linear Difference Equations

$$\sum_{k=0}^N a_k y[n-k] = \sum_{k=0}^M b_k x[n-k]$$

Example: $y[n] = x[n] + 0.1y[n-1]$

$$H(z) = \frac{b_0 + b_1 z^{-1} + \dots + b_M z^{-M}}{a_0 + a_1 z^{-1} + \dots + a_N z^{-N}} = \frac{b_0}{a_0} \frac{\prod_{k=1}^M (1 - c_k z^{-1})}{\prod_{k=1}^N (1 - d_k z^{-1})}$$



Magnitude Response

Magnitude of products is product of magnitudes

$$|H(e^{j\omega})| = \left| \frac{b_0}{a_0} \right| \cdot \frac{\prod_{k=0}^M |1 - c_k e^{-j\omega}|}{\prod_{k=0}^N |1 - d_k e^{-j\omega}|}$$

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Consider one of the poles:

$$|1 - d_k e^{-j\omega}| = |e^{+j\omega} - d_k| = |v_1|$$

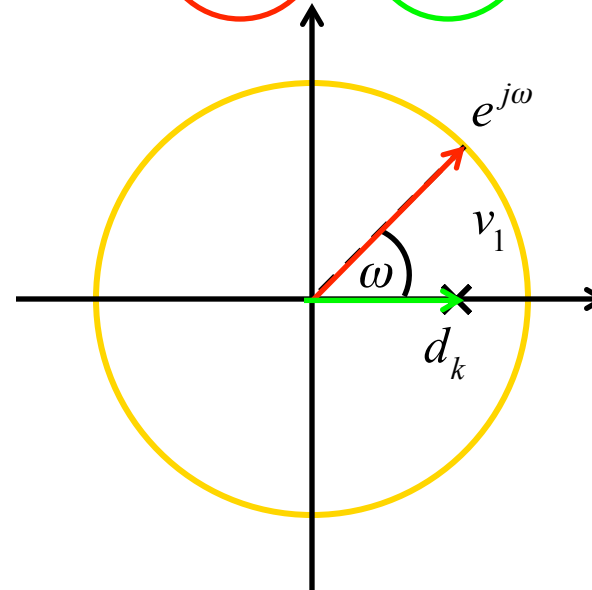
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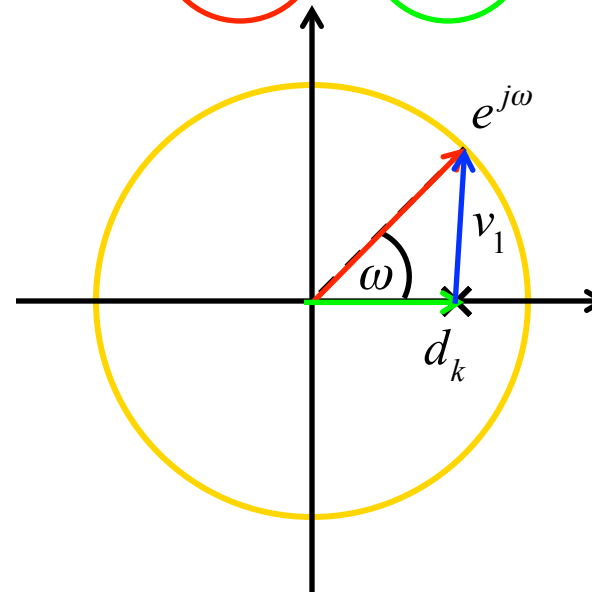
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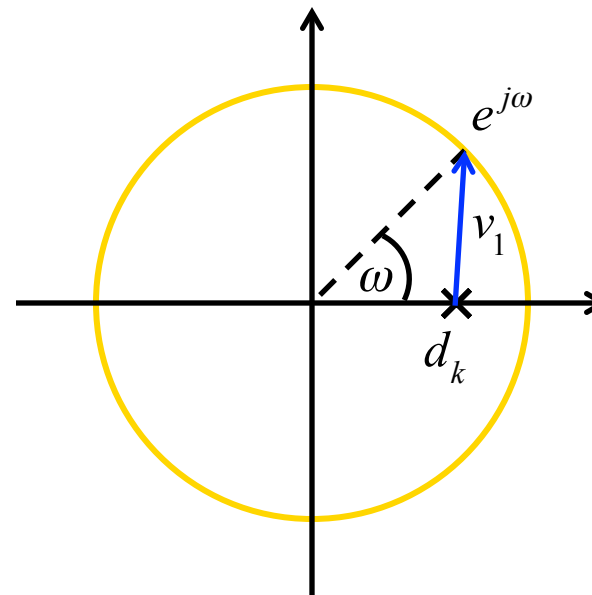
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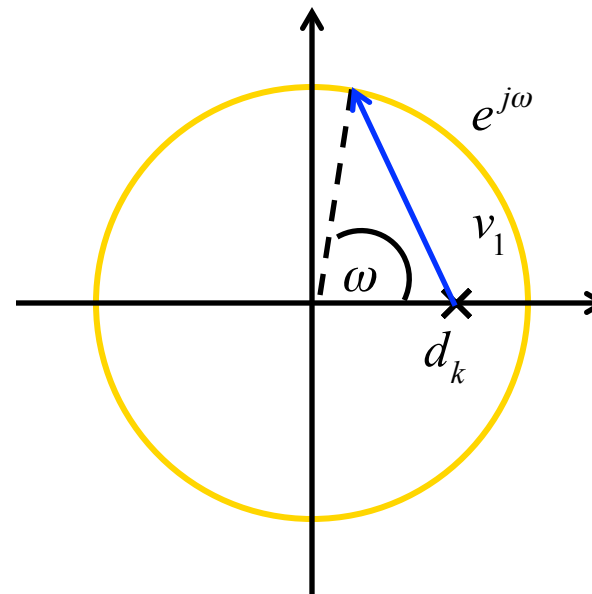
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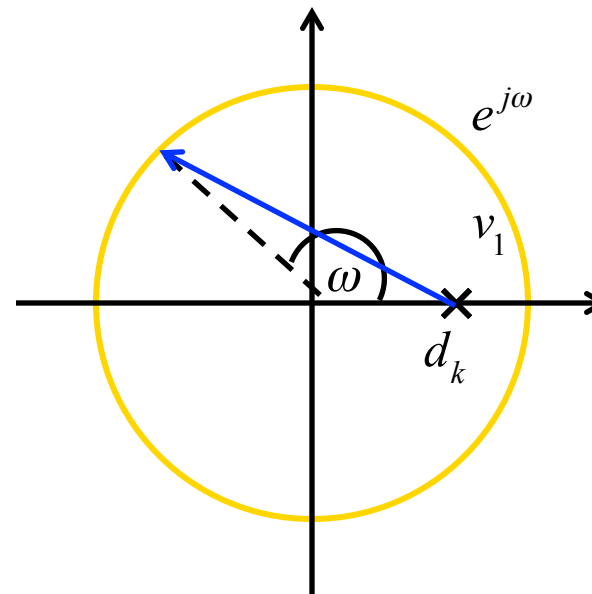
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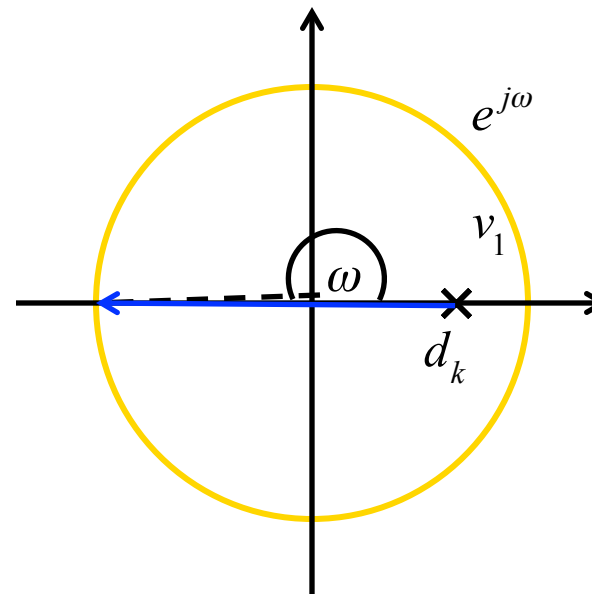
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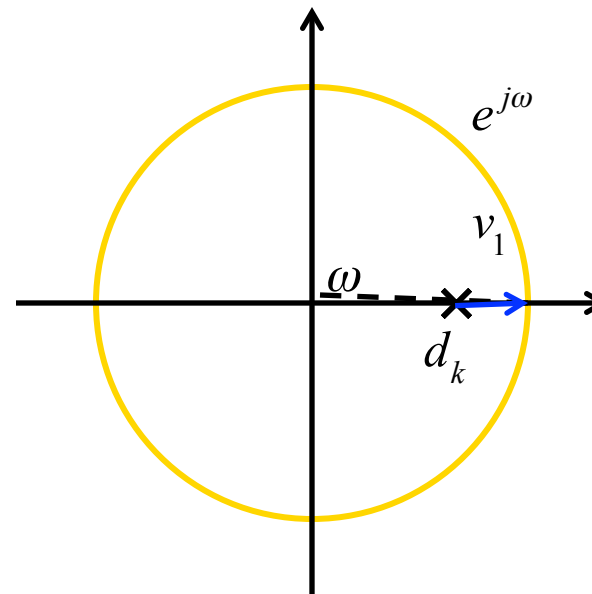
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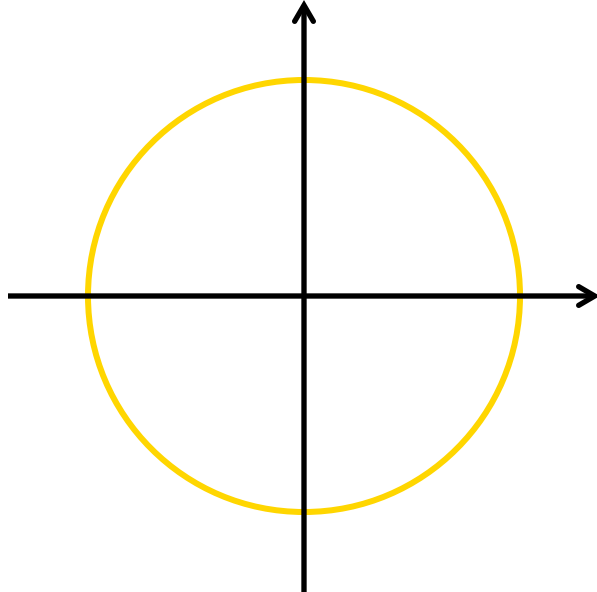
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Magnitude Response Example

$$H(z) = 0.05 \frac{1 + z^{-1}}{1 - 0.9z^{-1}}$$

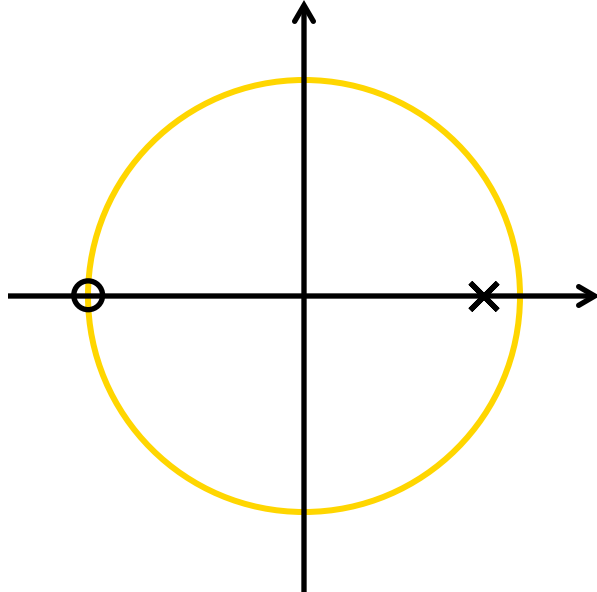
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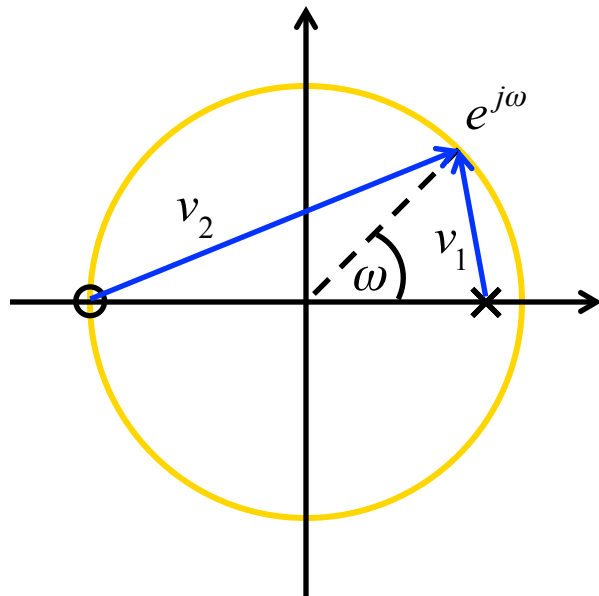
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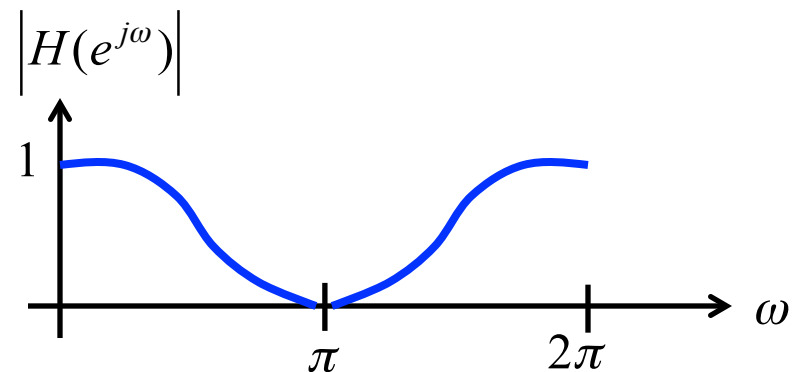
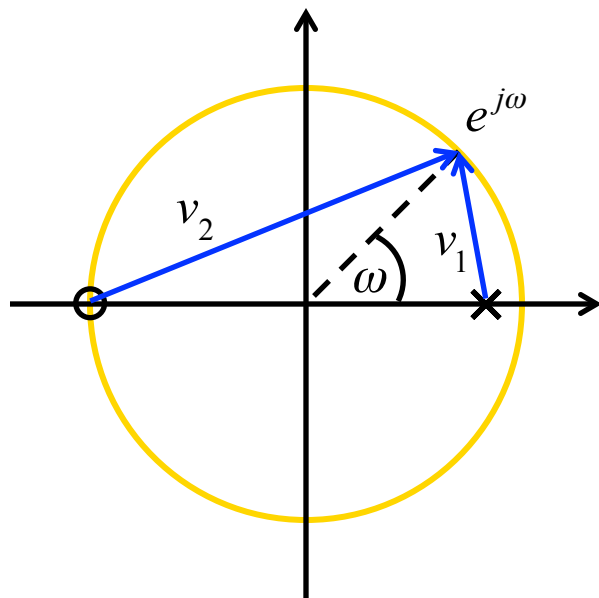
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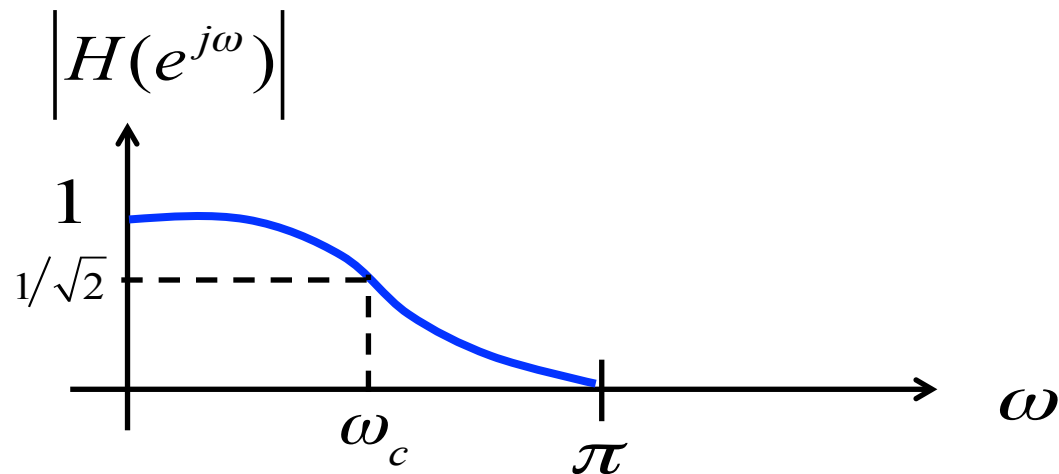


Simple Low Pass Filter

$$H_{LP}(z) = \frac{1 - \alpha}{2} \frac{1 + z^{-1}}{1 - \alpha z^{-1}} \quad |\alpha| < 1$$

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ω_c is the 3dB cutoff frequency

$$\alpha = \frac{1 - \sin(\omega_c)}{\cos(\omega_c)}$$



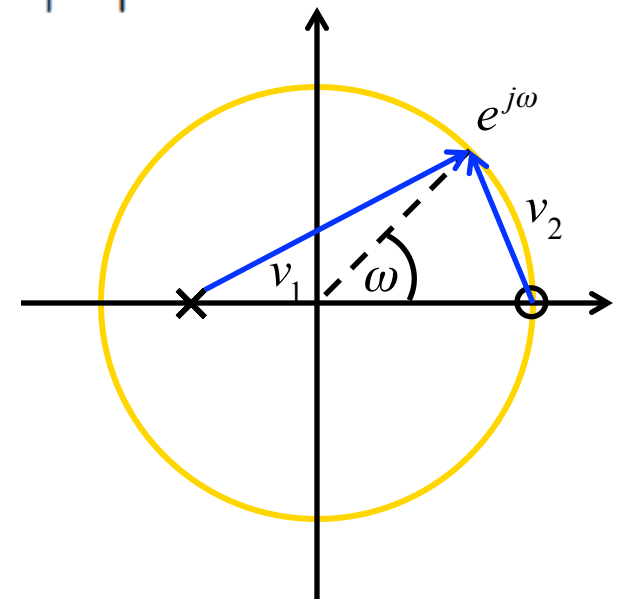
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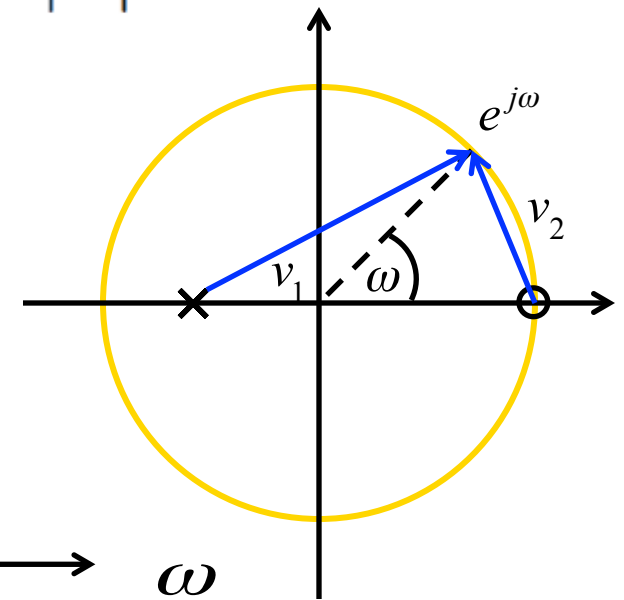
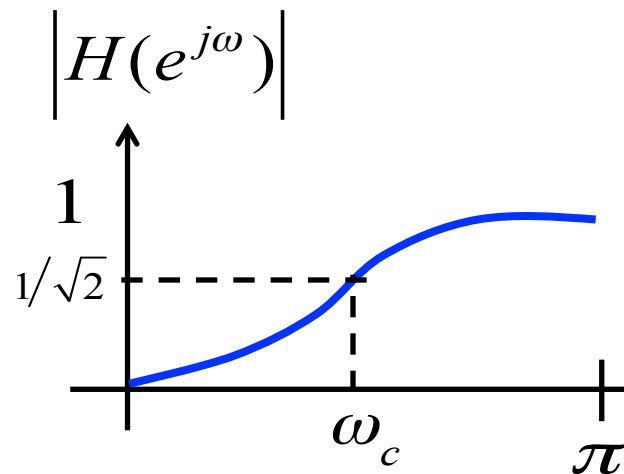
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Simple Band-Stop (Notch) Filter

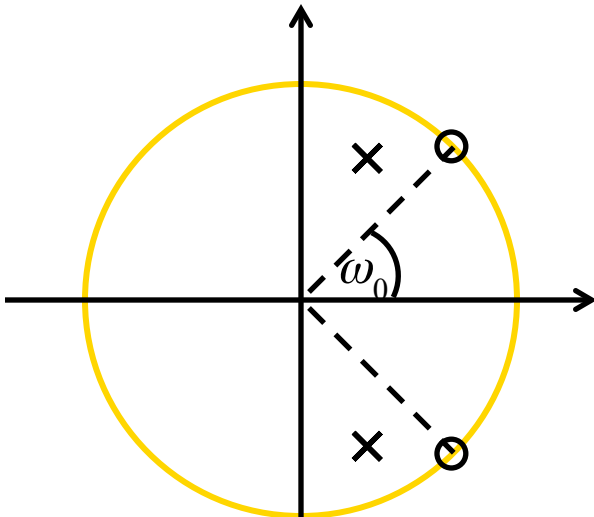
$$H_{BS}(z) = \frac{1 + \alpha}{2} \frac{1 - 2\beta z^{-1} + z^{-2}}{1 - \beta(1 + \alpha)z^{-1} + \alpha z^{-2}} \quad \begin{array}{l} |\alpha| < 1 \\ |\beta| < 1 \end{array}$$

Note: $1 - 2\beta z^{-1} + z^{-2} = (1 - e^{j\omega_0} z^{-1})(1 - e^{-j\omega_0} z^{-1})$
 $\cos(\omega_0) = \beta$

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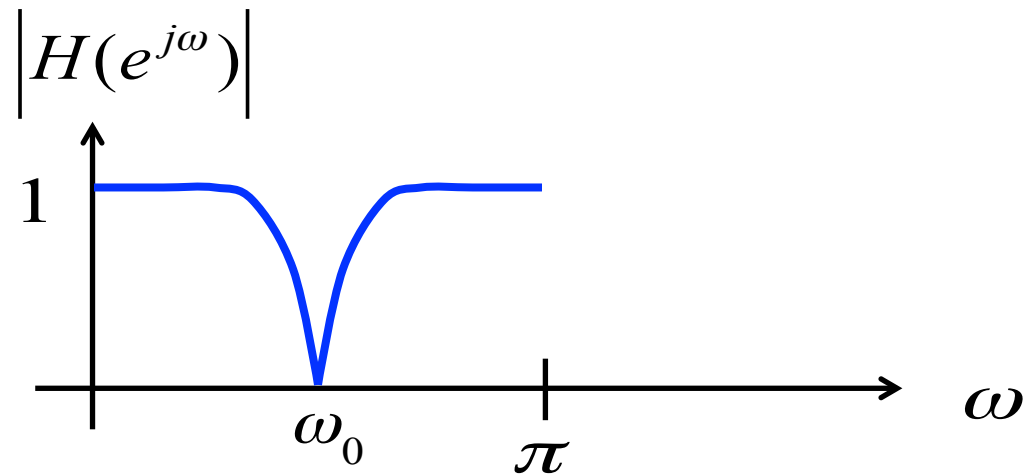
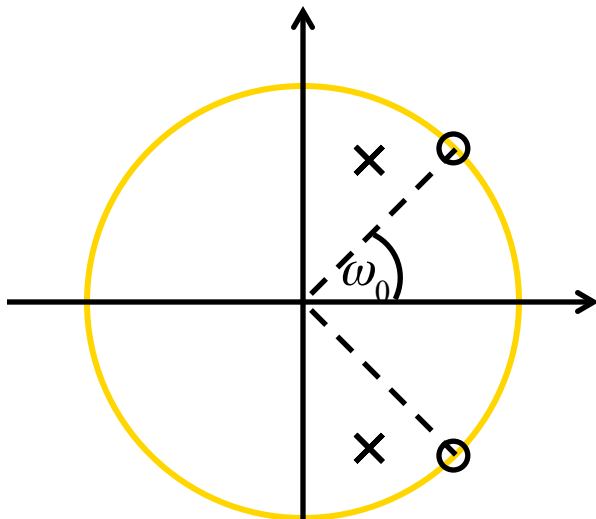
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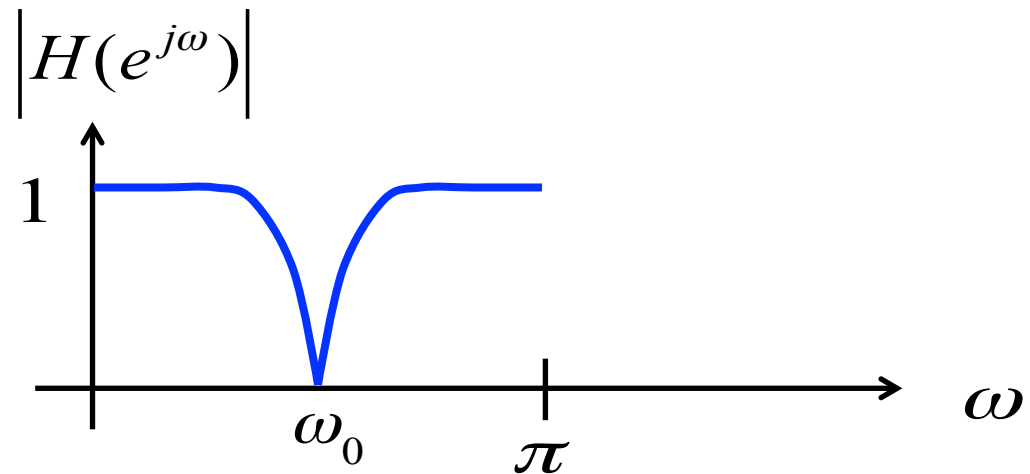
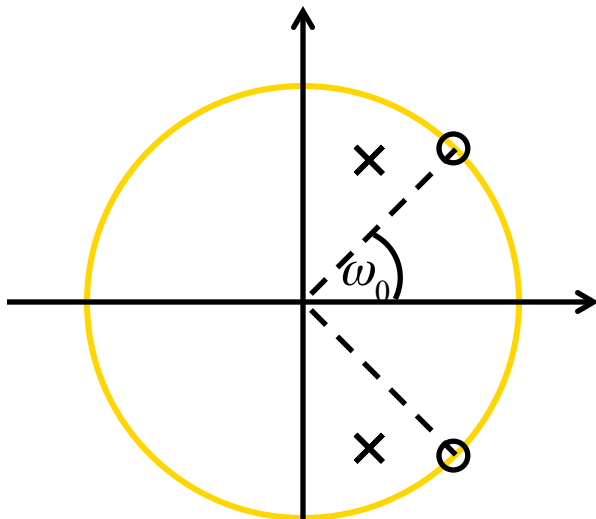


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Note:

$$H_{BS}(\mp 1) = \frac{1 + \alpha}{2} \frac{2 \pm 2\beta}{(1 + \alpha)(1 \pm \beta)} = 1$$

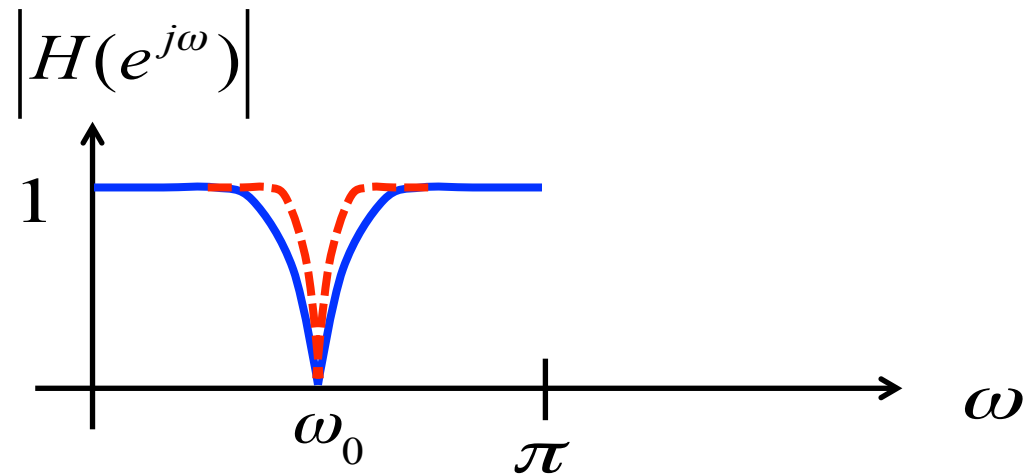
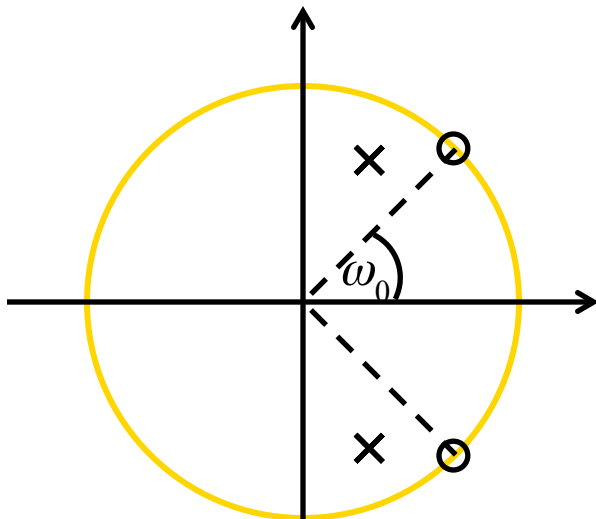


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Note: As $\alpha \rightarrow 1$ poles approach zeros

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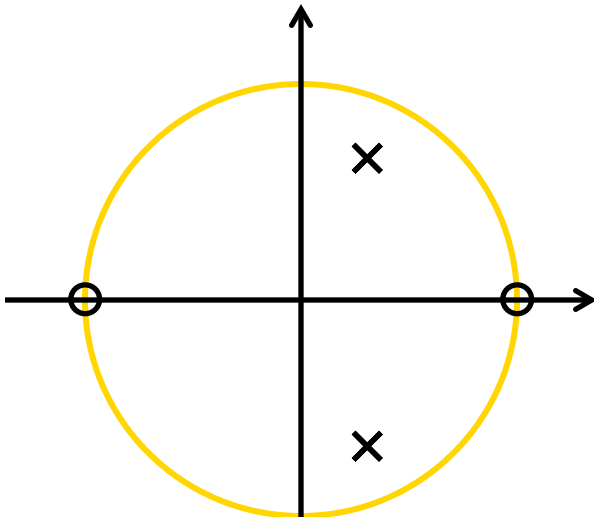


Simple Band-Pass Filter

$$H_{BP}(z) = \frac{1 - \alpha}{2} \frac{1 - z^{-2}}{1 - \beta(1 + \alpha)z^{-1} + \alpha z^{-2}} \quad \begin{array}{l} |\alpha| < 1 \\ |\beta| < 1 \end{array}$$

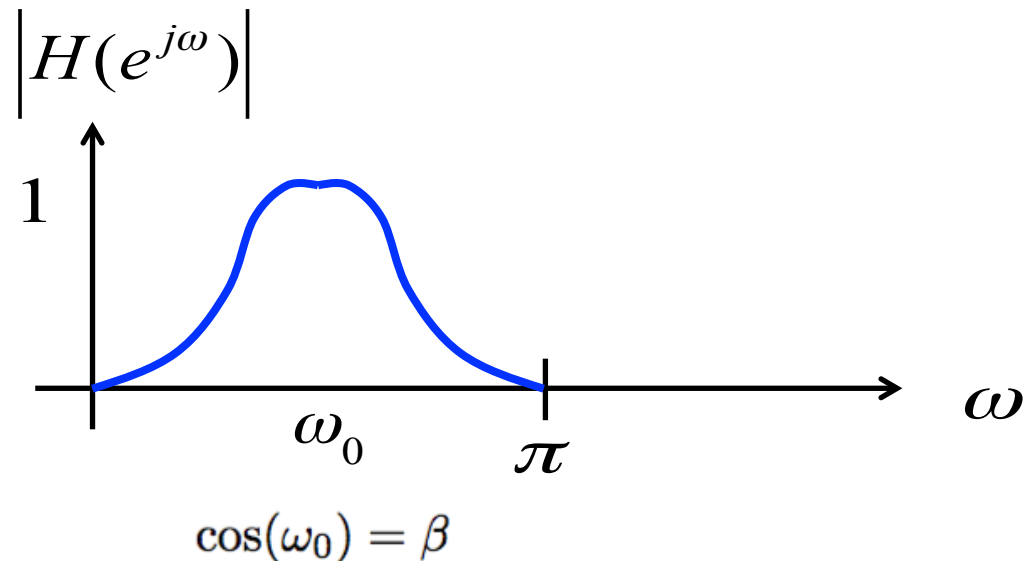
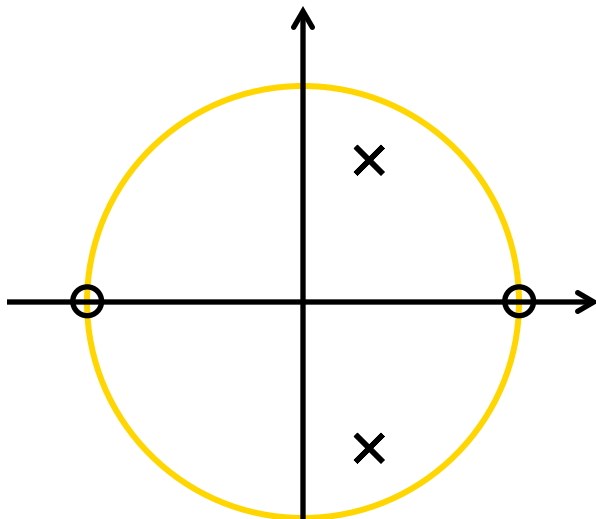
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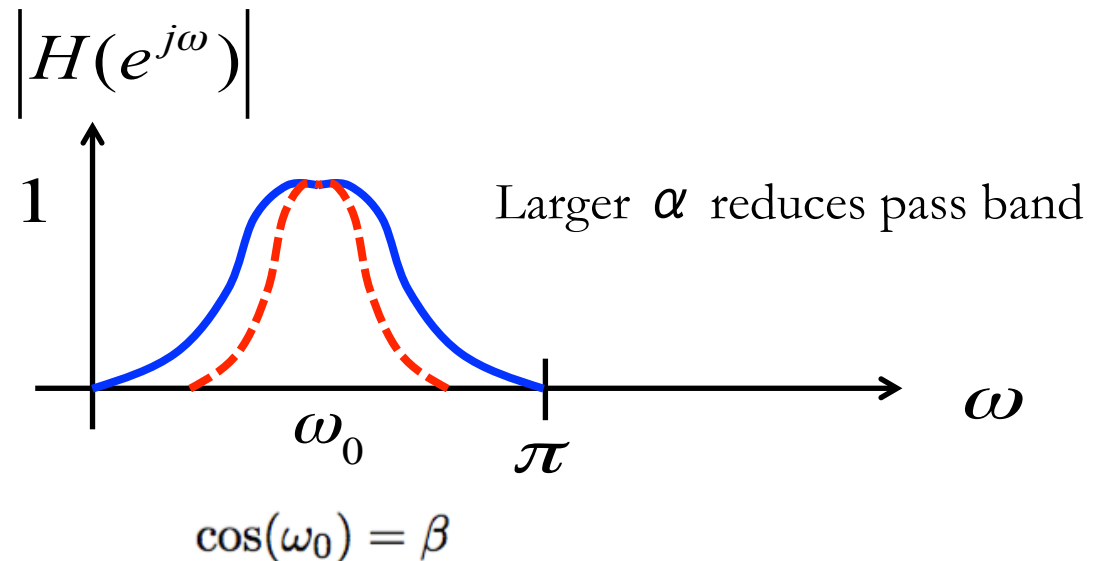
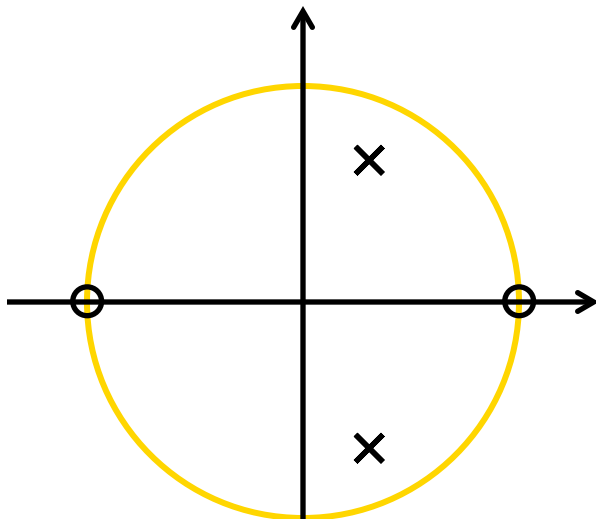
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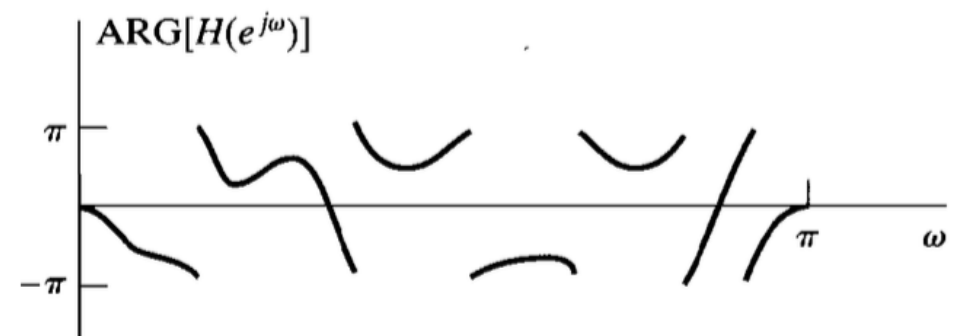
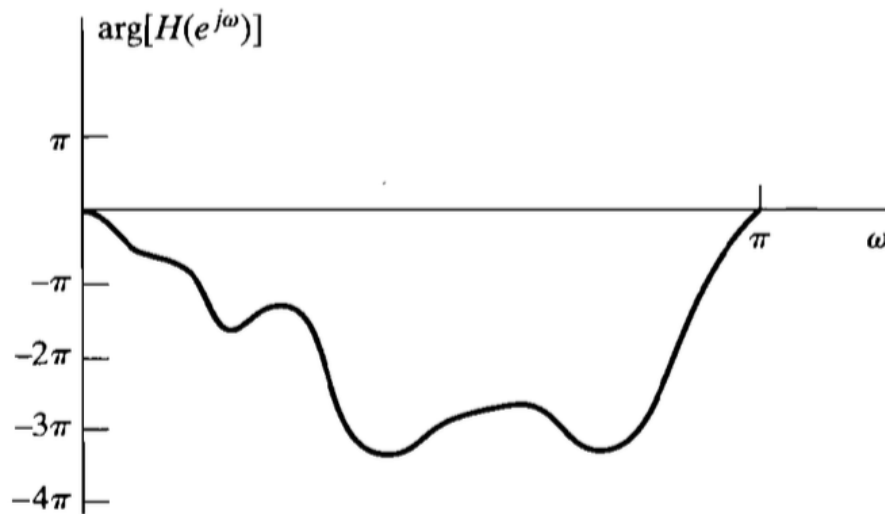
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Phase Response

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$$-\pi < \text{ARG}[H(e^{j\omega})] \leq \pi.$$



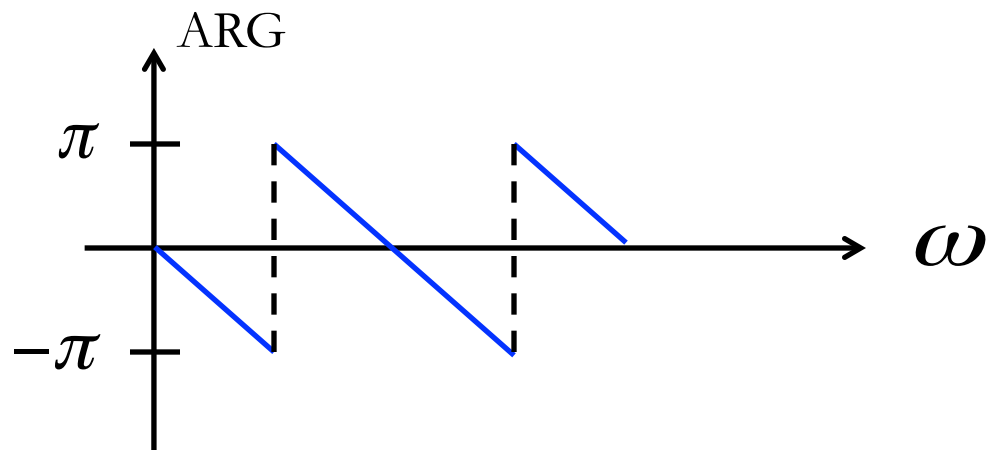
Phase Response Example

$$H(e^{j\omega}) = e^{j\omega n_d} \leftrightarrow h[n] = \delta[n - n_d]$$

$$|H(e^{j\omega})| = 1$$

$$\arg[H(e^{j\omega})] = -\omega n_d$$

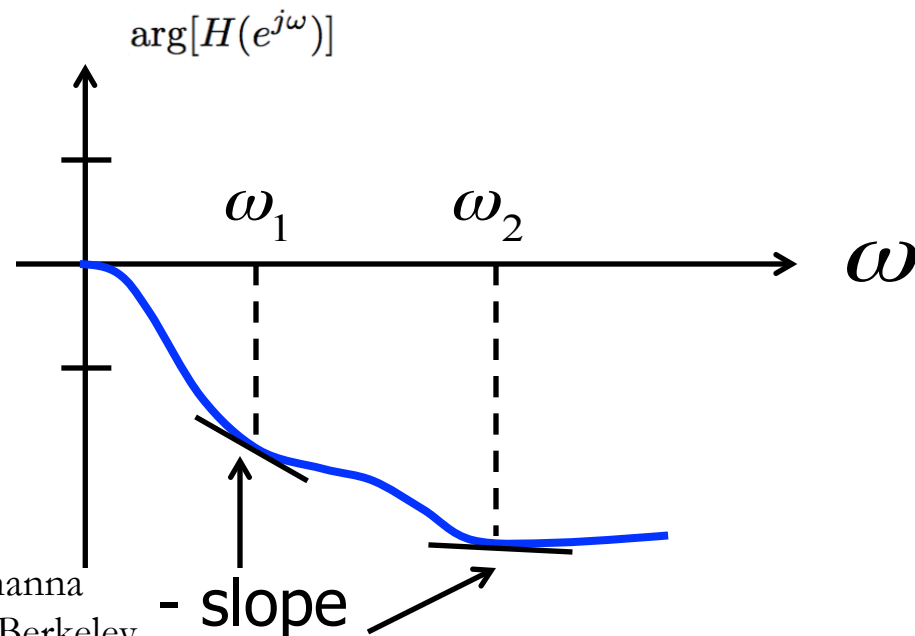
ARG is the wrapped phase
arg is the unwrapped phase



Group Delay

- General phase response at a given frequency can be characterized with group delay, which is related to phase

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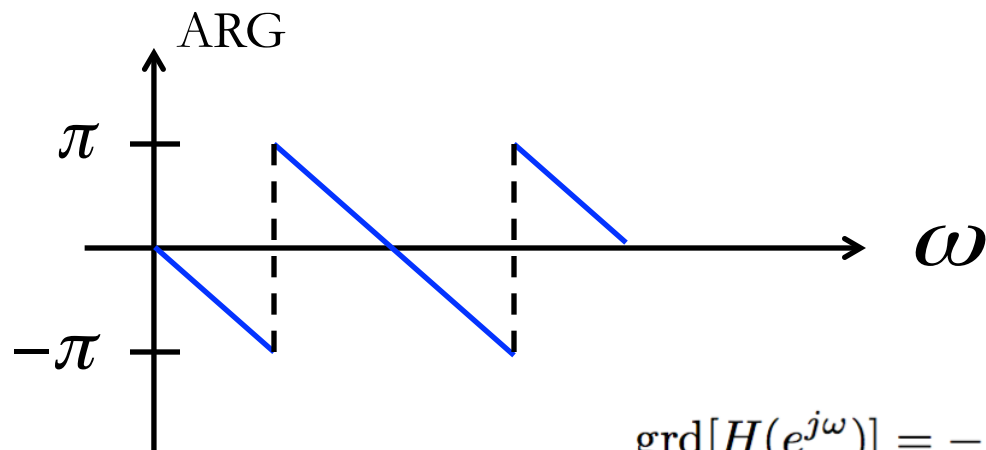
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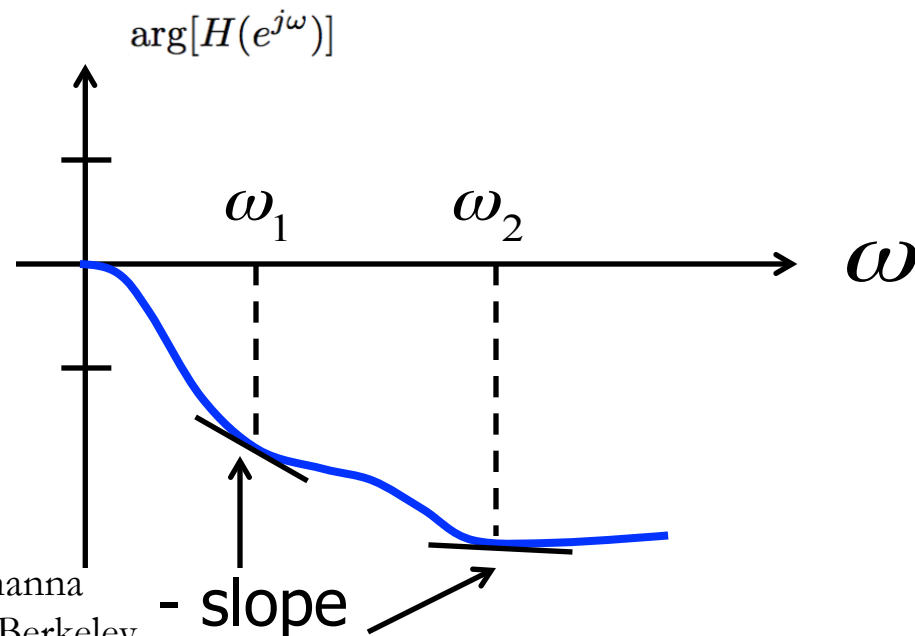
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For linear phase system, group delay is n_d

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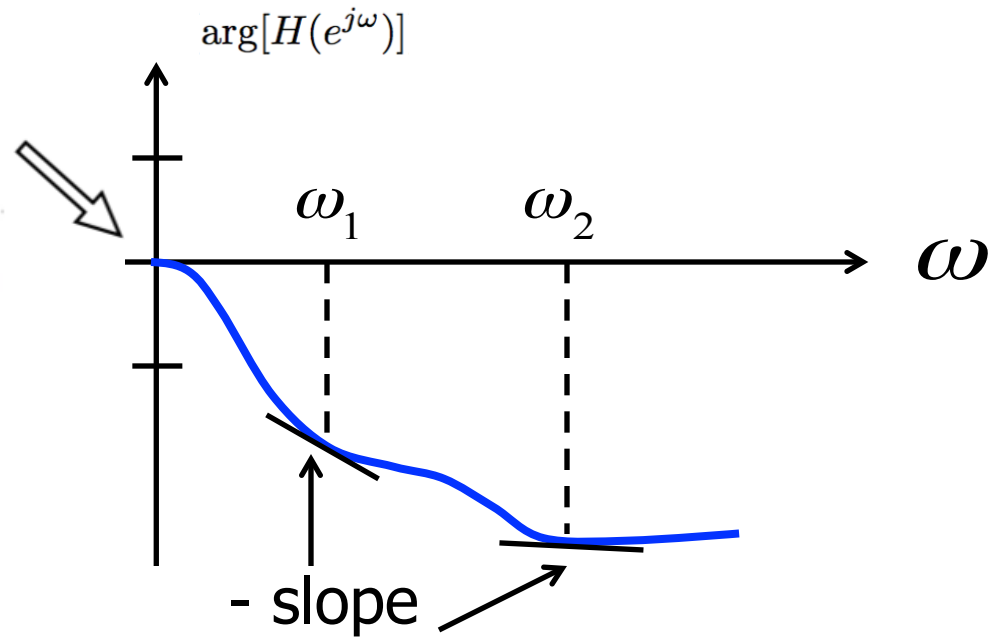
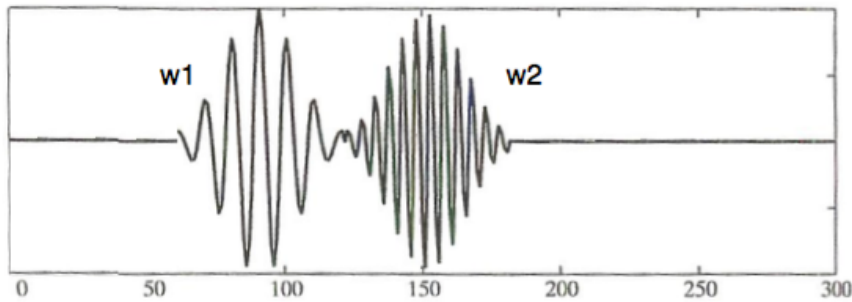
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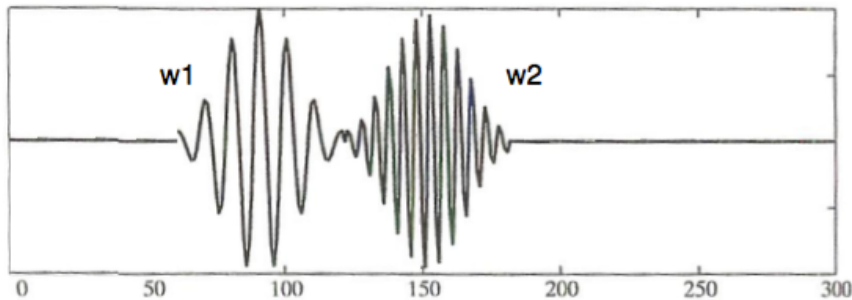
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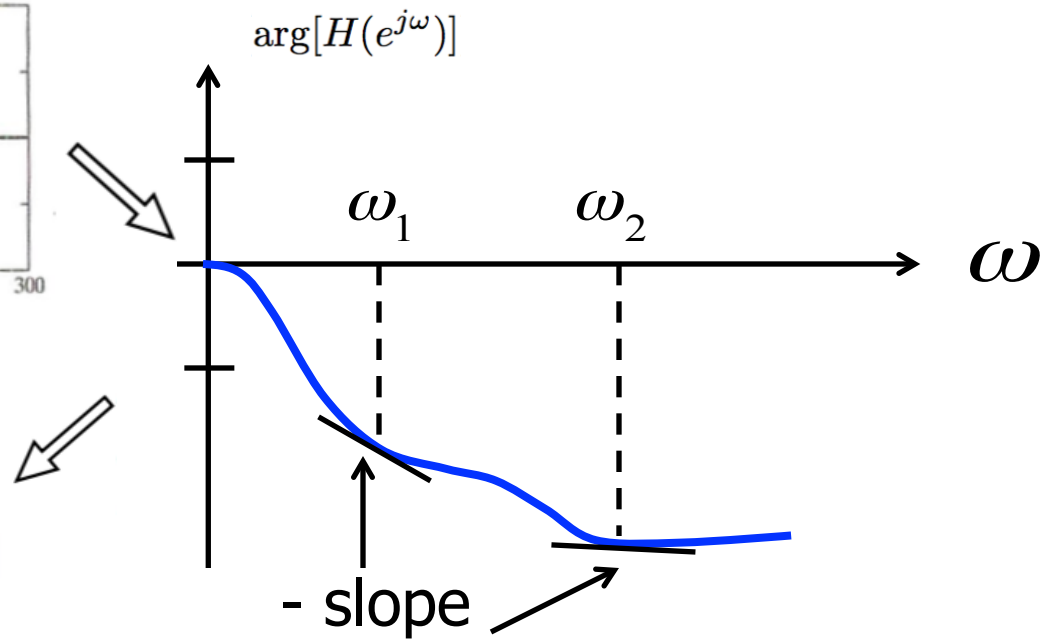
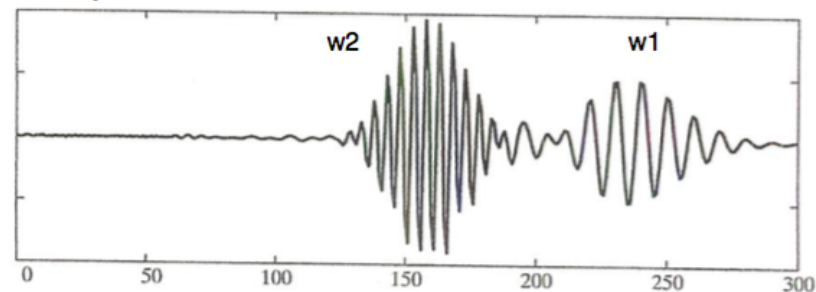
Group Delay

$$\text{grd}[H(e^{j\omega})] = -\frac{d}{d\omega} \{\arg[H(e^{j\omega})]\}$$

Input



Output





Group Delay Math

$$H(z) = \frac{b_0 \prod_{k=1}^M (1 - c_k z^{-1})}{a_0 \prod_{k=1}^N (1 - d_k z^{-1})}$$

$$H(e^{j\omega}) = \frac{b_0 \prod_{k=1}^M (1 - c_k e^{-j\omega})}{a_0 \prod_{k=1}^N (1 - d_k e^{-j\omega})}$$



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arg of products is sum of args

$$\arg[H(e^{j\omega})] = \sum_{k=1}^M \arg[1 - c_k e^{-j\omega}] - \sum_{k=1}^N \arg[1 - d_k e^{-j\omega}]$$

$$\text{grd}[H(e^{j\omega})] = \sum_{k=1}^M \text{grd}[1 - c_k e^{-j\omega}] - \sum_{k=1}^N \text{grd}[1 - d_k e^{-j\omega}]$$



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□ Look at each factor:

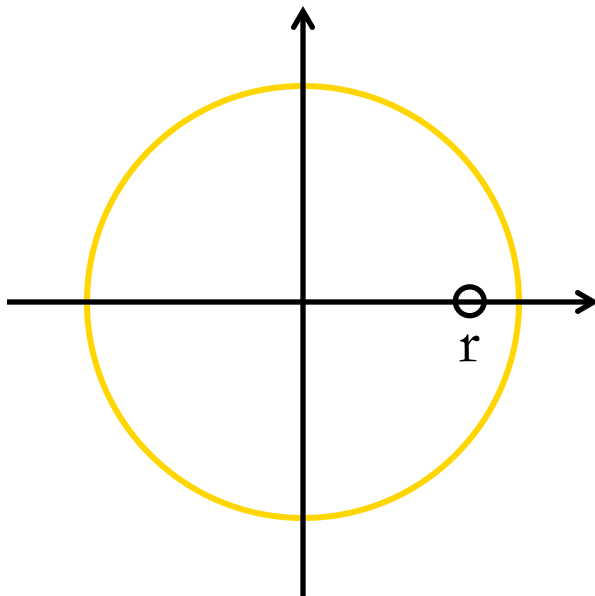
$$\arg[1 - re^{j\theta} e^{-j\omega}] = \tan^{-1} \left(\frac{r \sin(\omega - \theta)}{1 - r \cos(\omega - \theta)} \right)$$

$$\text{grd}[1 - re^{j\theta} e^{-j\omega}] = \frac{r^2 - r \cos(\omega - \theta)}{|1 - re^{j\theta} e^{-j\omega}|^2}$$

Example: Zero on Real Axis

- Geometric Interpretation for ($\theta = 0$)

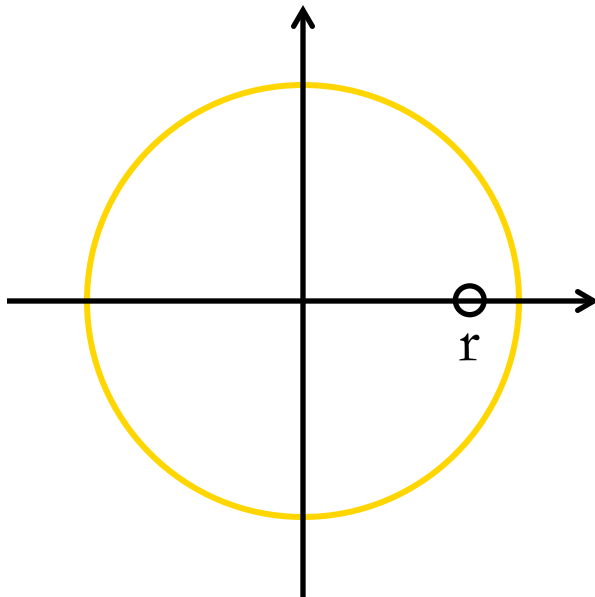
$$\arg[1 - re^{-j\omega}]$$



Example: Zero on Real Axis

- Geometric Interpretation for ($\theta = 0$)

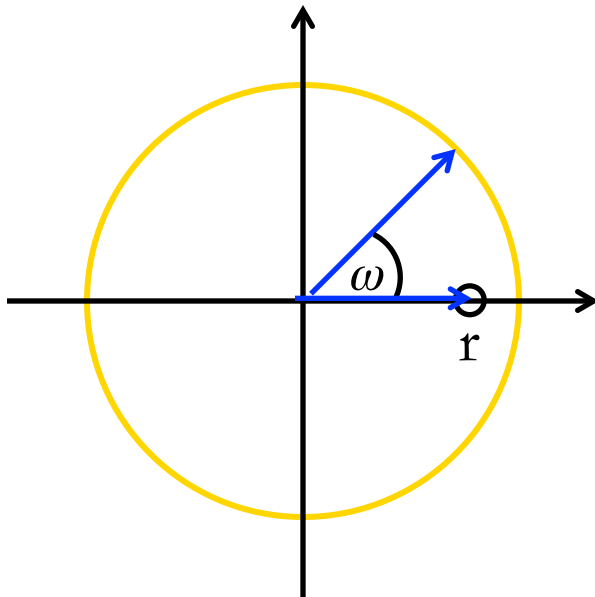
$$\arg[1 - re^{-j\omega}] = \arg[(e^{j\omega} - r)e^{-j\omega}] = \underbrace{\arg[e^{j\omega} - r]}_{\varphi} - \underbrace{\arg[e^{j\omega}]}_{\omega}$$



Example: Zero on Real Axis

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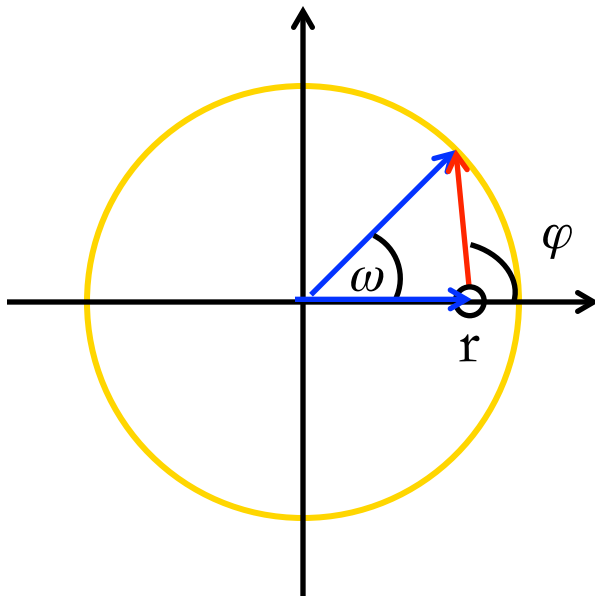
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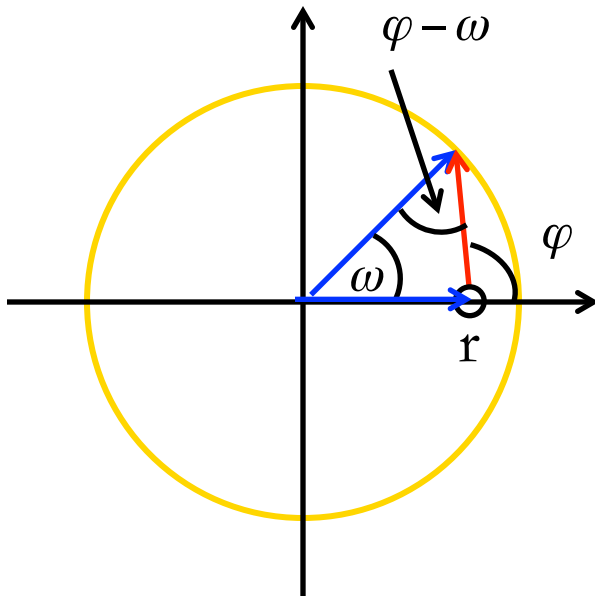
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Example: Zero on Real Axis

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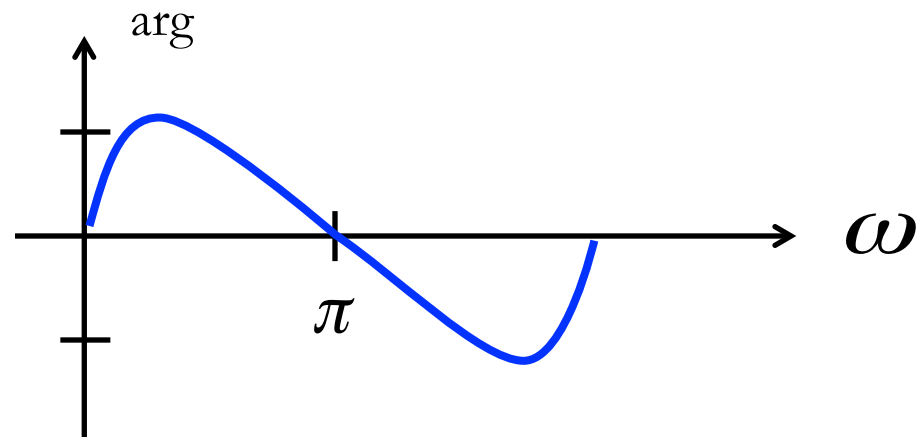
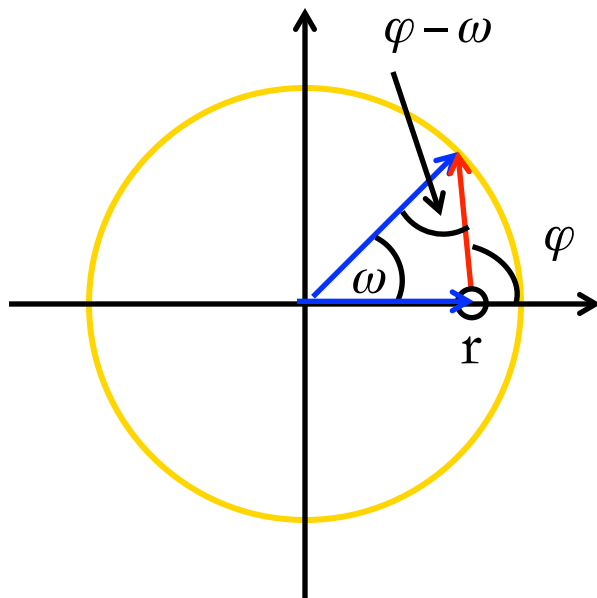
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Example: Zero on Real Axis

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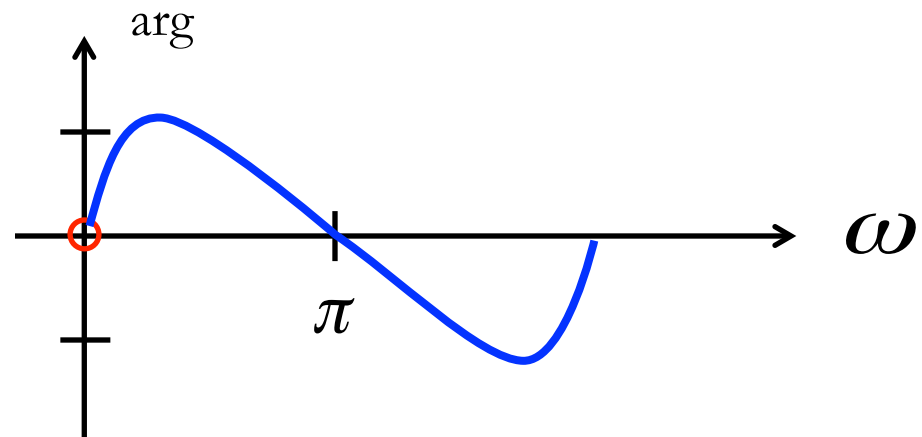
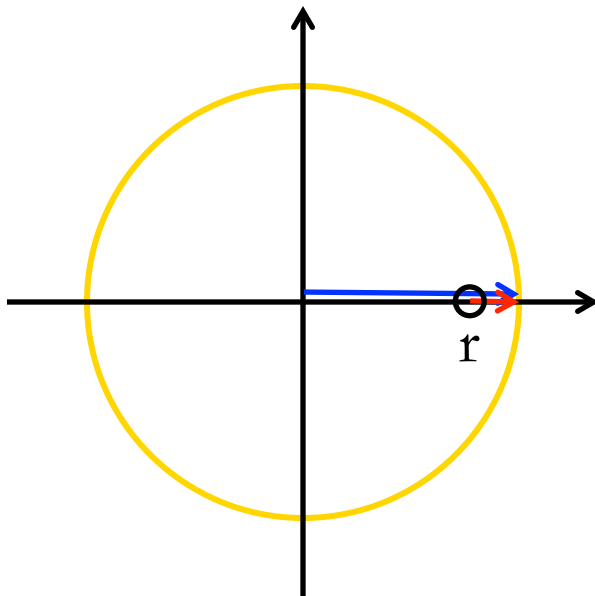


Example: Zero on Real Axis

- Geometric Interpretation for ($\theta = 0$)

$$\arg[1 - re^{-j\omega}] = \arg[(e^{j\omega} - r)e^{-j\omega}] = \underbrace{\arg[e^{j\omega} - r]}_{\varphi} - \underbrace{\arg[e^{j\omega}]}_{\omega}$$

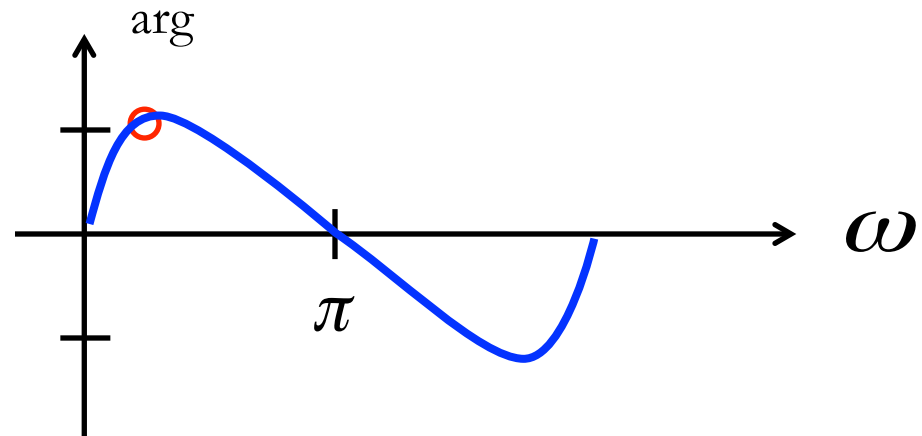
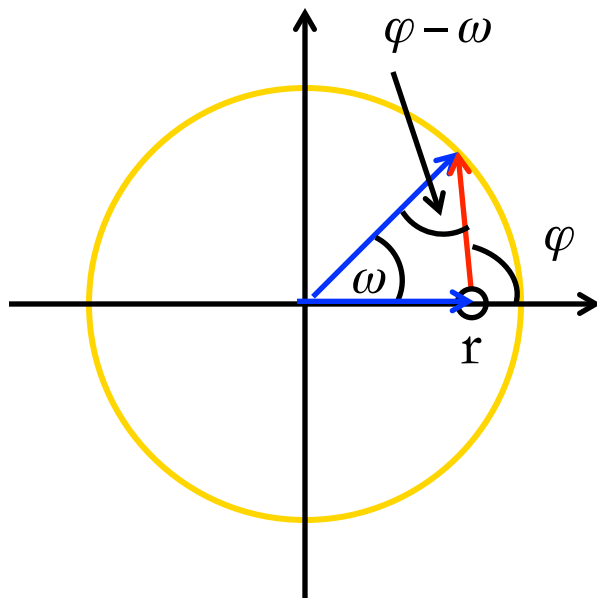
$\omega = 0$



Example: Zero on Real Axis

- Geometric Interpretation for ($\theta = 0$)

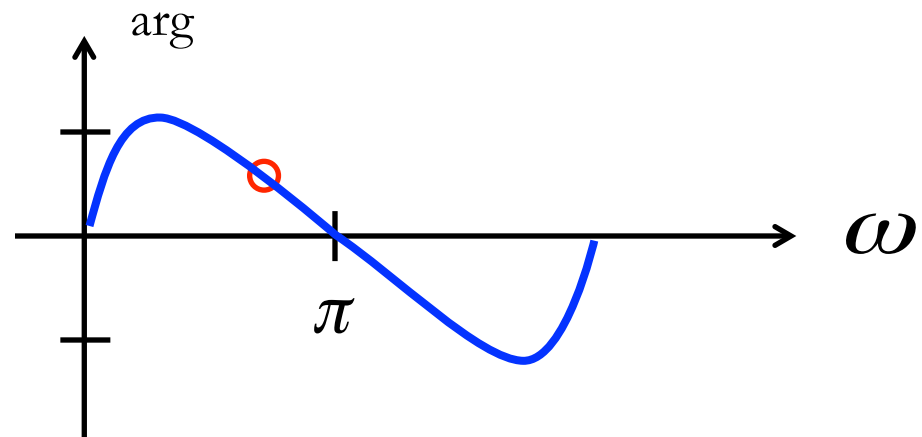
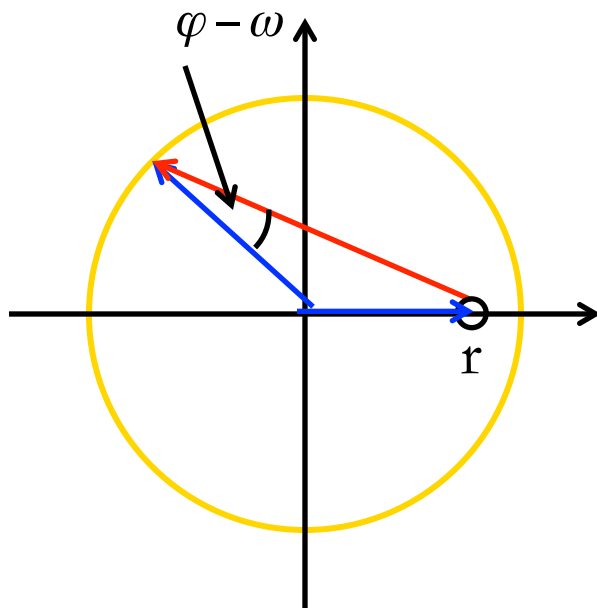
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Example: Zero on Real Axis

- Geometric Interpretation for ($\theta = 0$)

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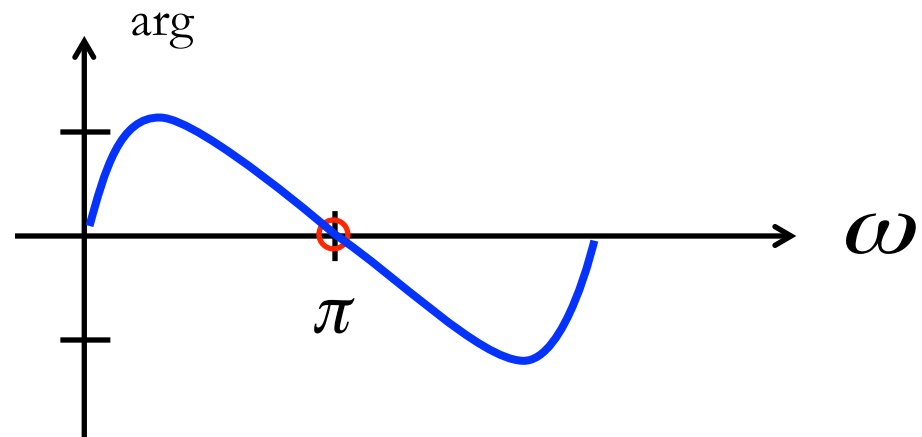
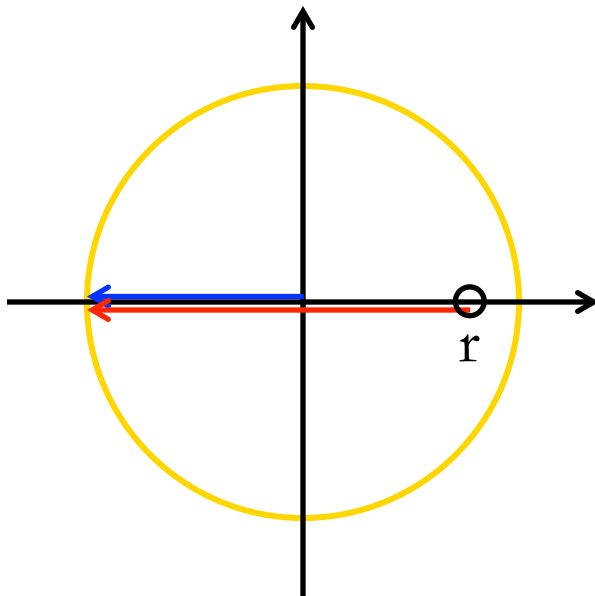


Example: Zero on Real Axis

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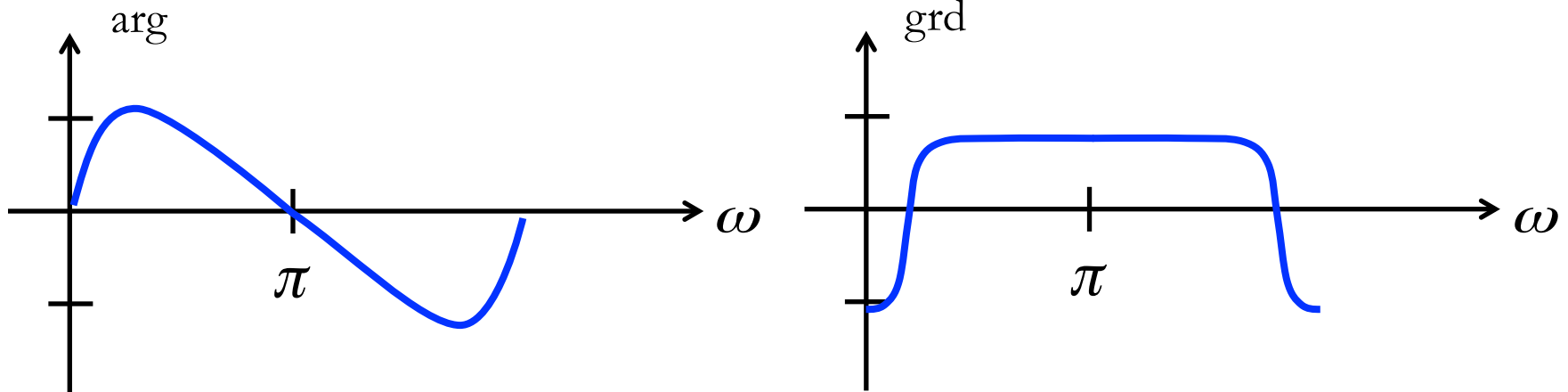
$$\omega = \pi$$



Example: Zero on Real Axis

- Geometric Interpretation for ($\theta = 0$)

$$\arg[1 - re^{-j\omega}] = \arg[(e^{j\omega} - r)e^{-j\omega}] = \underbrace{\arg[e^{j\omega} - r]}_{\varphi} - \underbrace{\arg[e^{j\omega}]}_{\omega}$$





Group Delay Math

$$\text{grd}[H(e^{j\omega})] = \sum_{k=1}^M \text{grd}[1 - c_k e^{-j\omega}] - \sum_{k=1}^N \text{grd}[1 - d_k e^{-j\omega}]$$

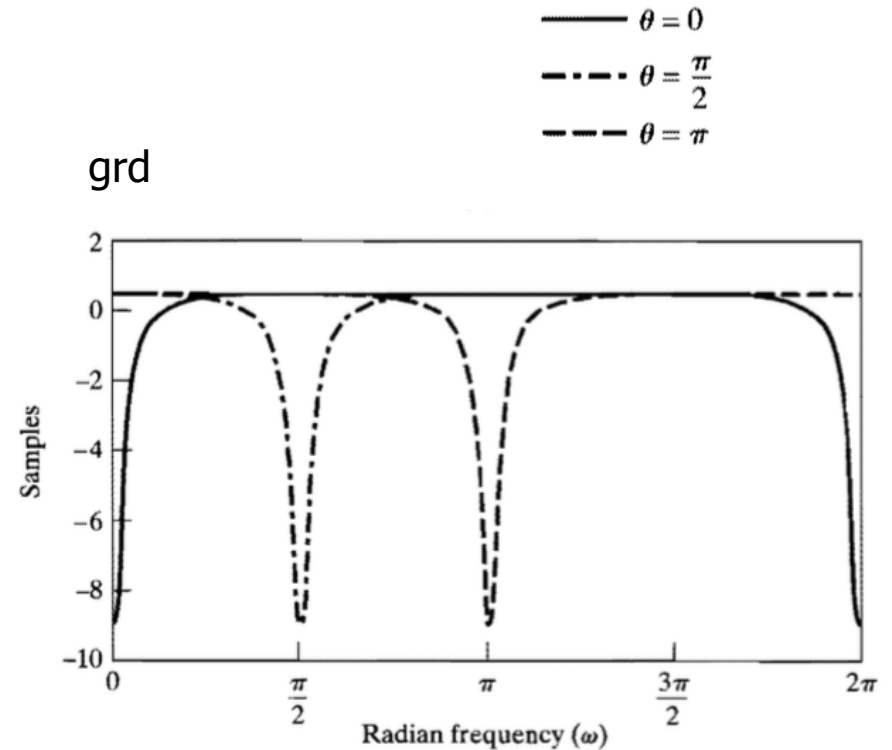
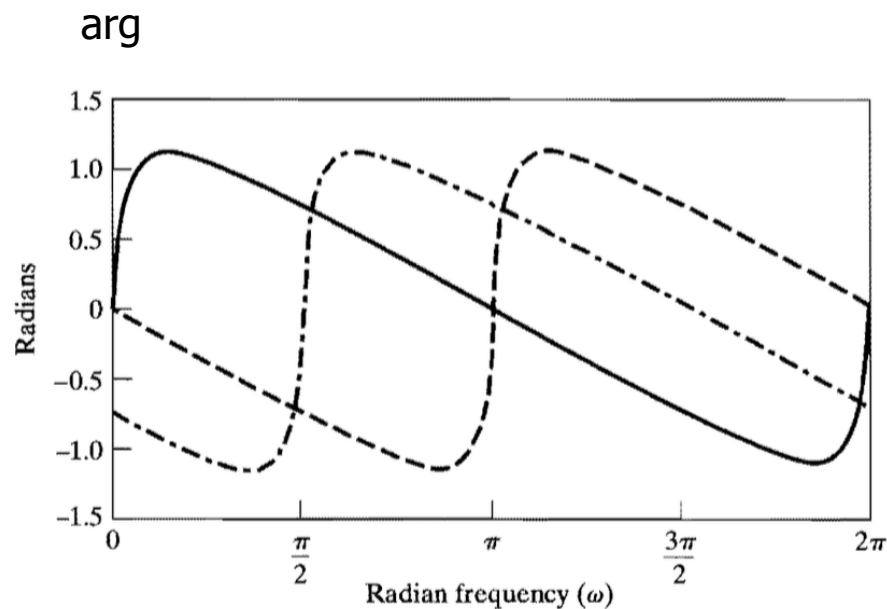
□ Look at each factor:

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$$\text{grd}[1 - re^{j\theta} e^{-j\omega}] = \frac{r^2 - r \cos(\omega - \theta)}{|1 - re^{j\theta} e^{-j\omega}|^2}$$

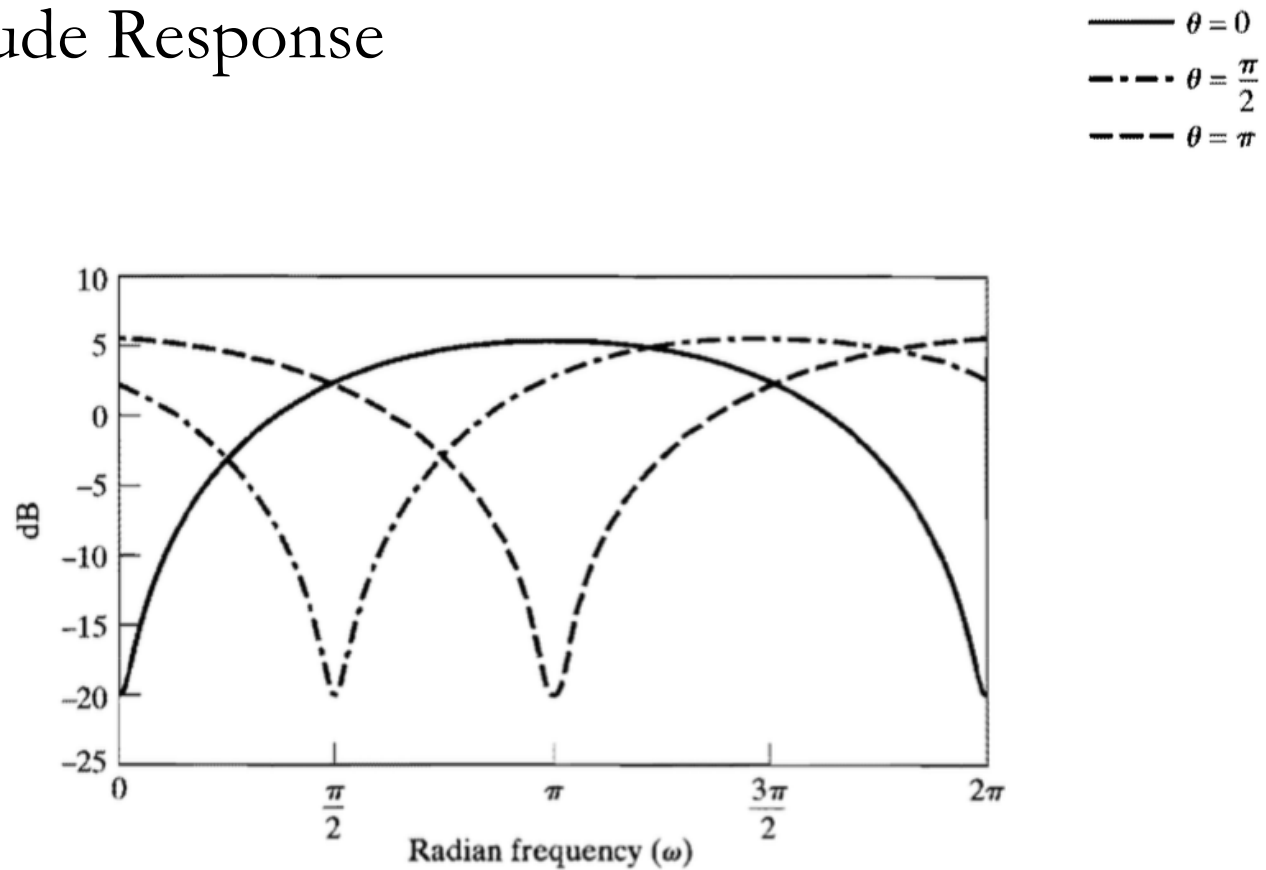
Example: Zero on Real Axis

□ For $\theta \neq 0$



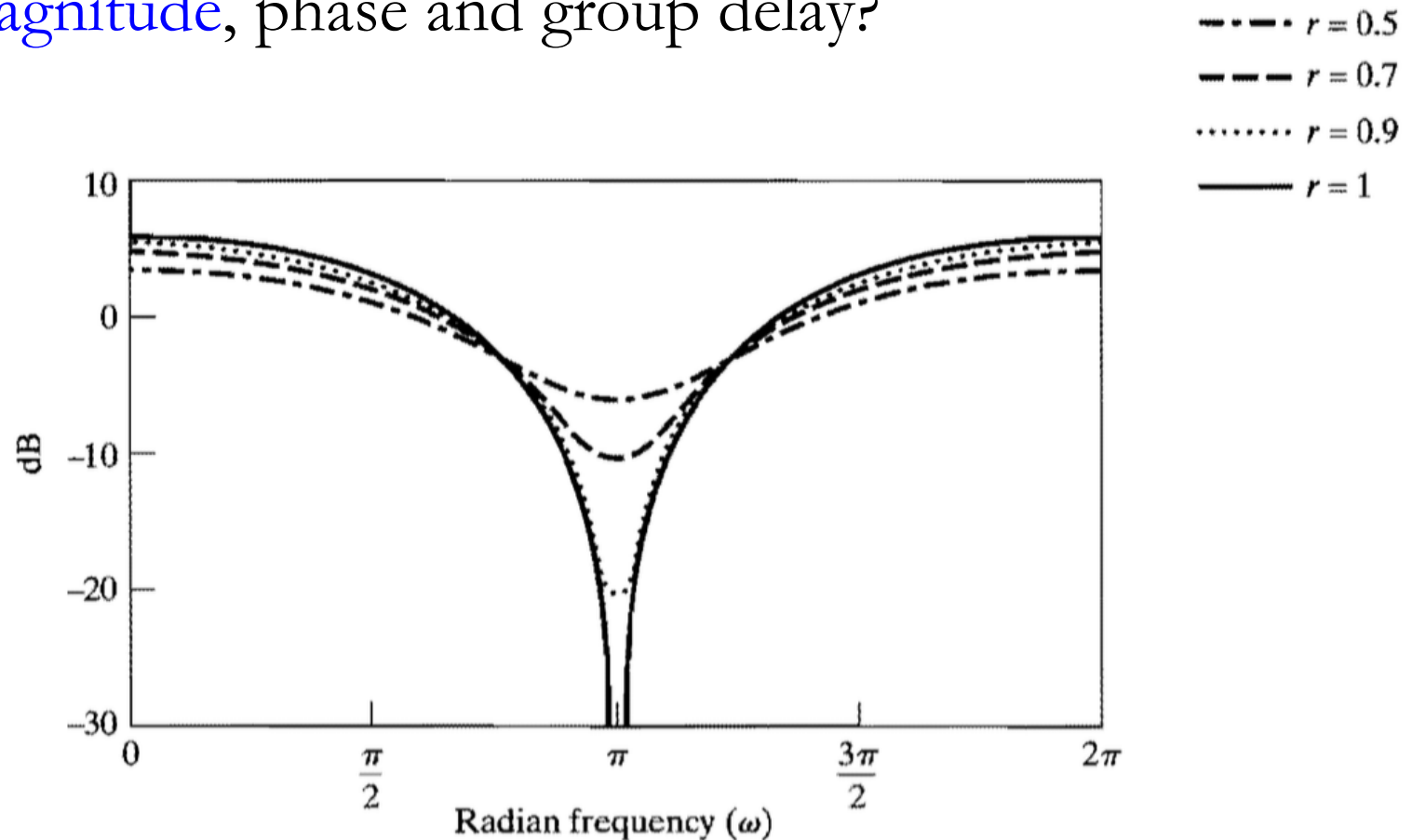
Example: Zero on Real Axis

□ Magnitude Response



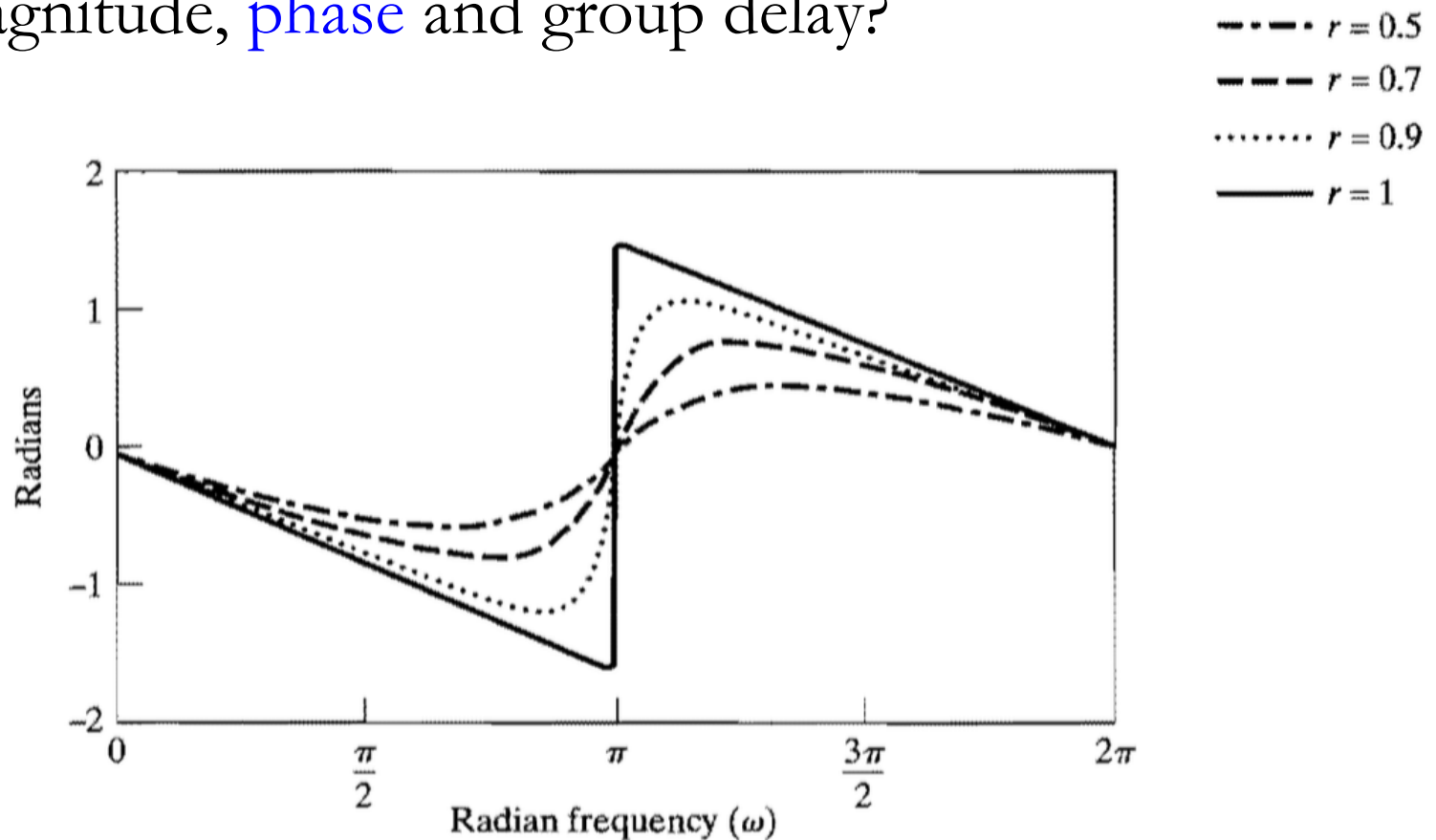
Example: Zero on Real Axis

- For $\theta = \pi$, how does zero location effect **magnitude**, phase and group delay?



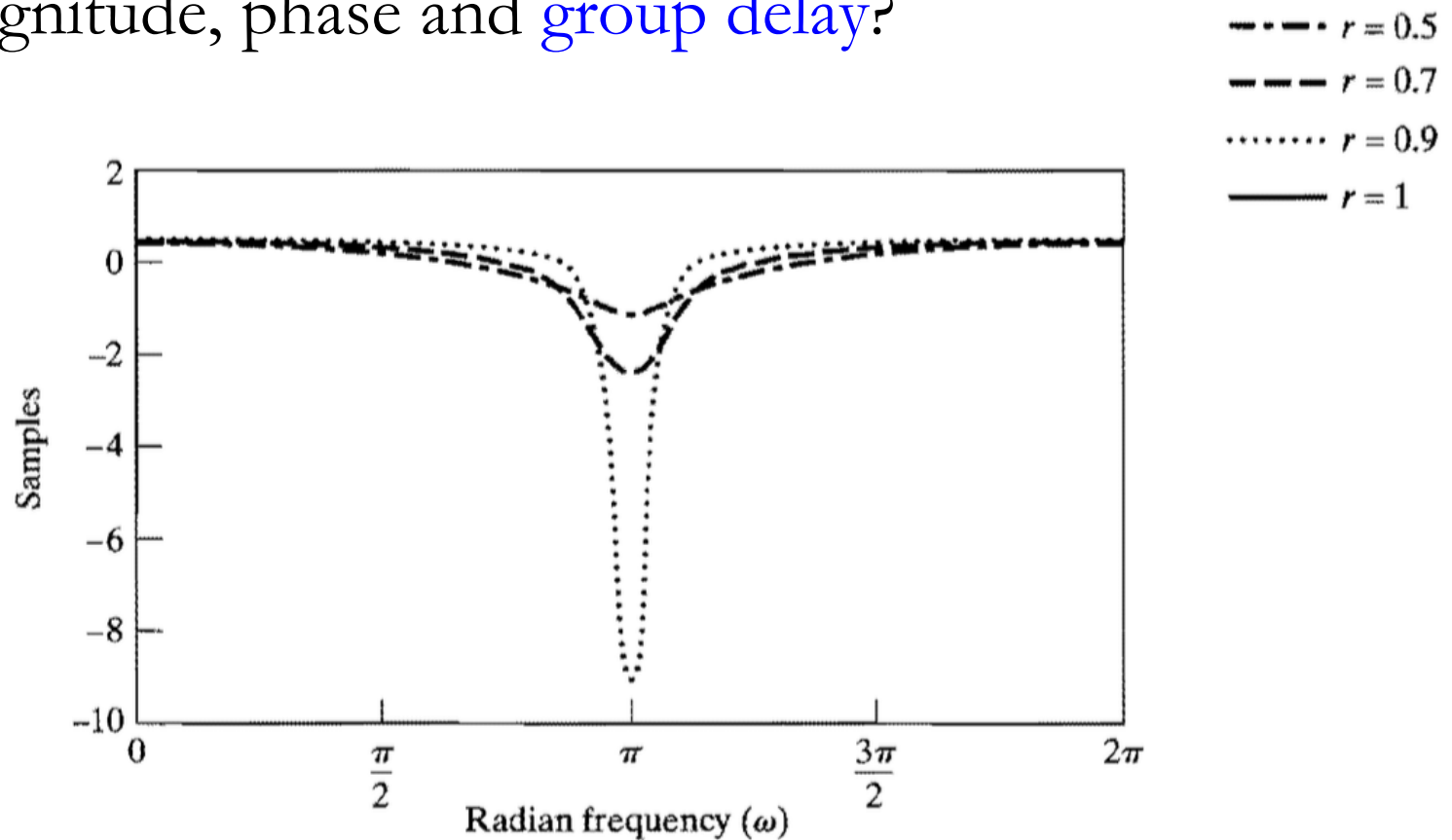
Example: Zero on Real Axis

- For $\theta = \pi$, how does zero location effect magnitude, **phase** and group delay?



Example: Zero on Real Axis

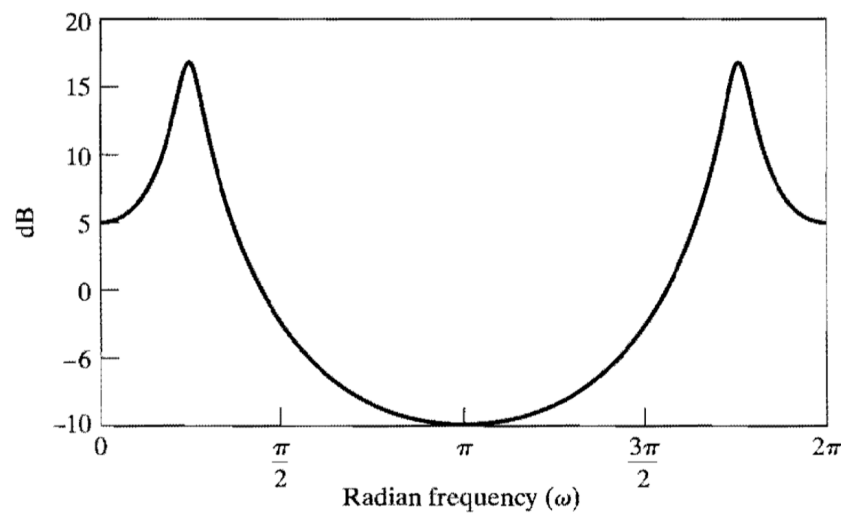
- For $\theta = \pi$, how does zero location effect magnitude, phase and group delay?



2nd Order IIR with Complex Poles

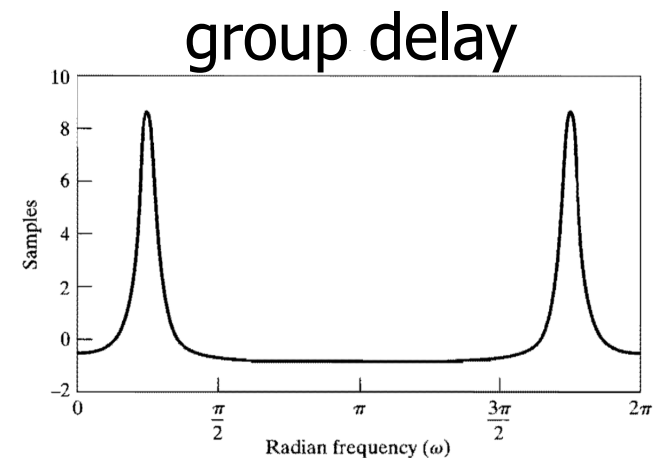
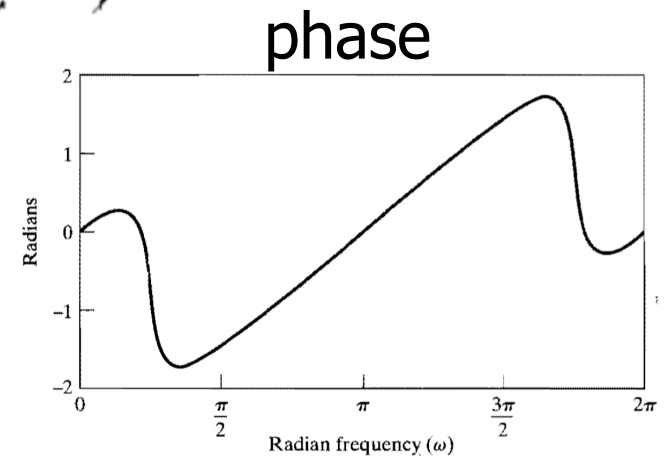
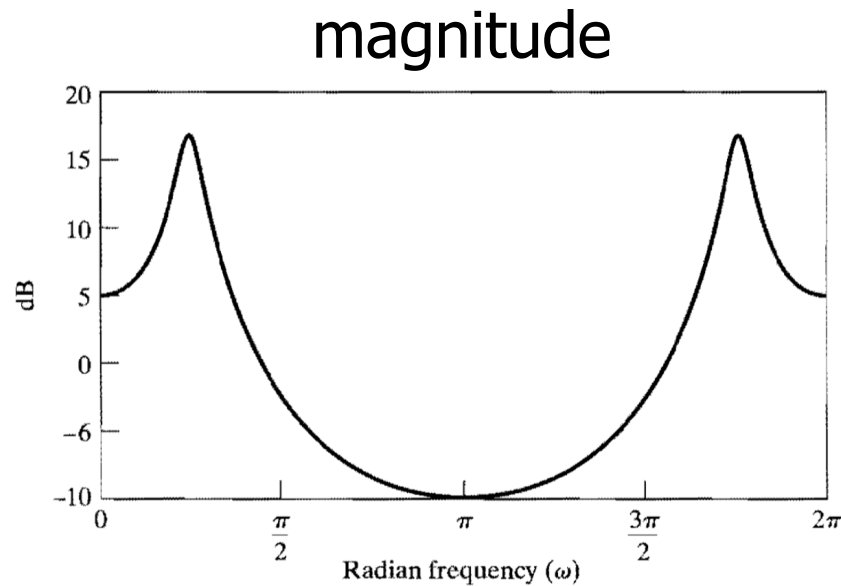
$$H(z) = \frac{1}{(1 - re^{j\theta}z^{-1})(1 - re^{-j\theta}z^{-1})}$$

magnitude



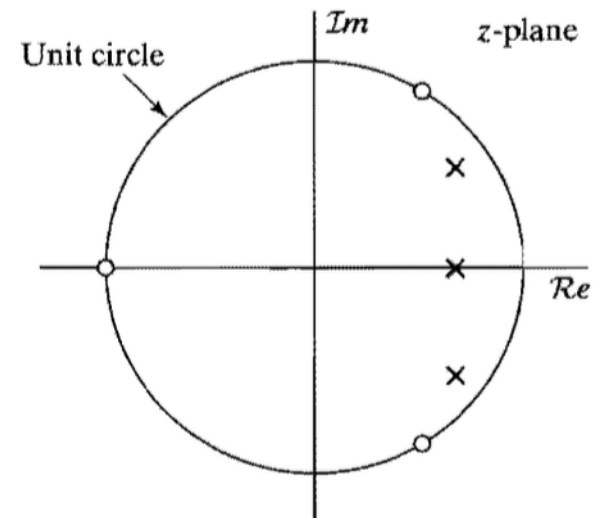
2nd Order IIR with Complex Poles

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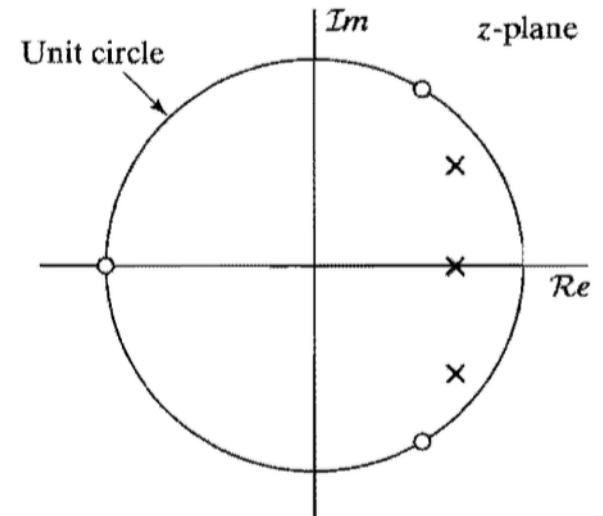
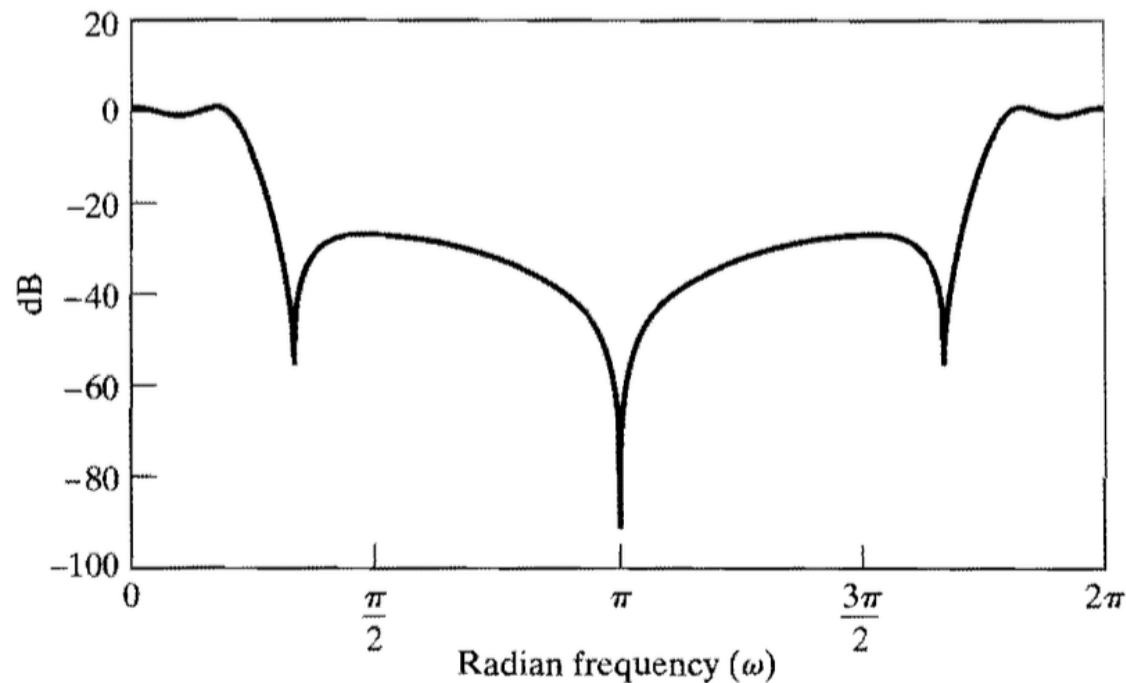
3rd Order IIR Example

$$H(z) = \frac{0.05634(1 + z^{-1})(1 - 1.0166z^{-1} + z^{-2})}{(1 - 0.683z^{-1})(1 - 1.4461z^{-1} + 0.7957z^{-2})}$$



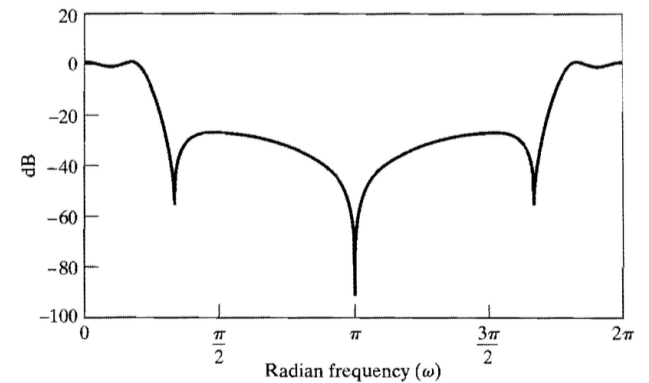
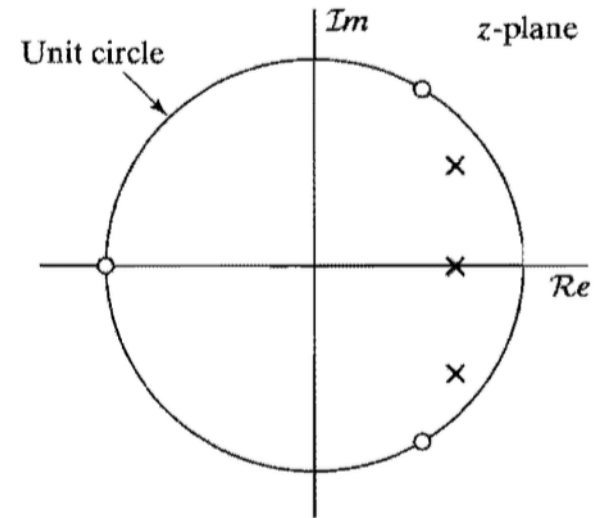
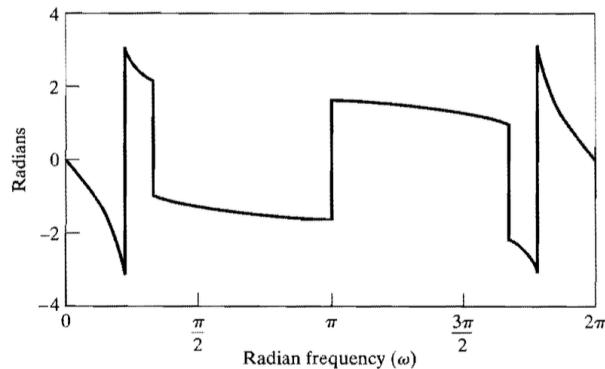
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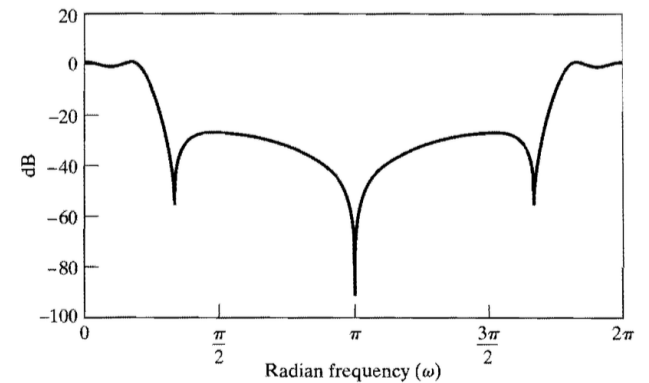
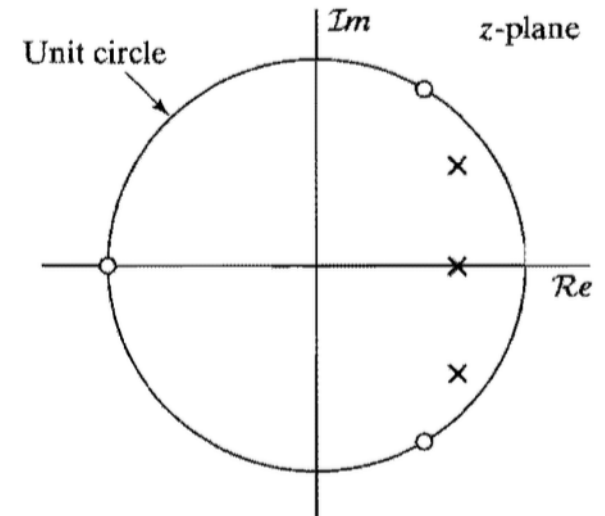
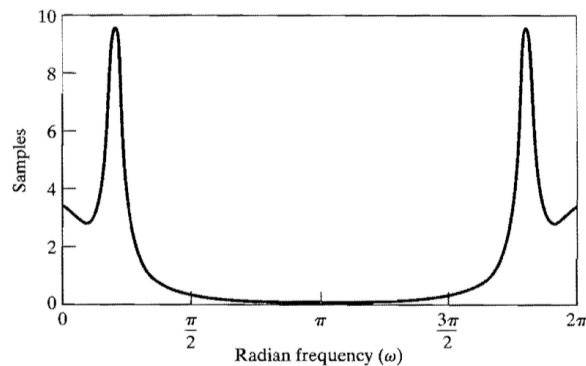
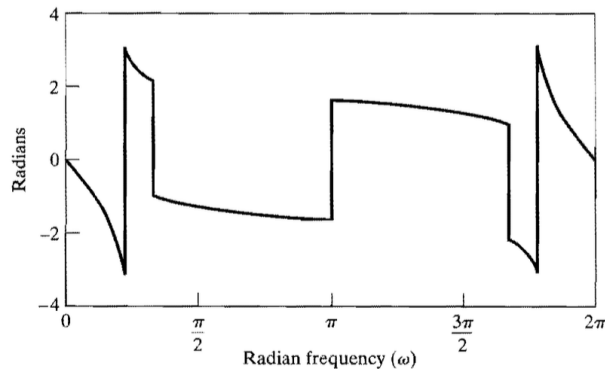
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Big Ideas

- ❑ Frequency Response of LTI Systems
 - Magnitude Response
 - Simple Filters
 - Phase Response
 - Group Delay
 - Example: Zero on Real Axis



Admin

- ❑ HW 5
 - Due Friday 2/23

- ❑ Homework solutions to be posted soon...