Table of contents

- Preface
- Each chapter ends with a Summary and References.
- Each Matlab section ends with Problems.
- B Background
- B.1 Complex Numbers
- B.2 Sinusoids
- B.3 Sketching Signals
- B.4 Cramer's Rule
- B.5 Partial Fraction Expansion
- B.6 Vectors and Matrices
- B.7 Miscellaneous
- Matlab Session B Elementary Operations
- B.M.1 Matlab Overview
- B.M.2 Calculator Operations
- B.M.3 Vector Operations
- B.M.4 Simple Plotting
- B.M.5 Element-by-Element Operations
- B.M.6 Matrix Operations
- B.M.7 Partial Fraction Expansions
- 1 Signals and Systems
- 1.1 Size of a Signal
- 1.2 Some Useful Signal Operations
- 1.3 Classification of Signals
- 1.4 Some Useful Signal Models
- 1.5 Even and Odd Functions
- 1.6 Systems
- 1.7 Classification of Systems
- 1.8 System Model: Input-Output Description
- 1.9 Internal and External Descriptions of a System
- 1.10 Internal Description: The State-Space Description
- Matlab Session 1 Working with Functions
- 1.M.1 Inline Functions
- 1.M.2 Relational Operators and the Unit Step Function
- 1.M.3 Visualizing Operations on the Independent Variable
- 1.M.4 Numerical Integration and Estimating Signal Energy
- 2 Time-Domain Analysis of Continuous-Time Systems
- 2.1 Introduction
- 2.2 System Response to Internal Conditions: The Zero-Input Response
- 2.3 The Unit Impulse Response h(t)
- 2.4 System Response to External Input: Zero-State Response
- 2.5 Classical Solution of Differential Equations
- 2.6 System Stability
- 2.7 Intuitive Insights into System Behavior
- 2.8 Appendix 2.1: Determining the Impulse Response

- **Matlab Session 2 M-Files**
- **2.M.1 Script M-Files**
- **2.M.2 Function M-Files**
- **2.M.3 For Loops**
- **2.M.4 Graphical Understanding of Convolution**
- **3 Time-Domain Analysis of Discrete-Time Systems**
- **3.1 Introduction**
- **3.2 Useful Signal Operations**
- **3.3 Some Useful Discrete-Time Signal Models**
- **3.4 Examples of Discrete-Time Systems**
- **3.5 Discrete-Time System Equations**
- **3.6 System Response to Internal Conditions: The Zero-Input Response**
- **3.7 The Unit Impulse Response h[n]**
- **3.8 System Response to External Input: The Zero-State Response**
- **3.9 Classical Solution of Linear Difference Equations**
- **3.10 System Stability: The External (BIBO) Stability Criterion**
- **3.11 Intuitive Insights into System Behavior**
- **3.12 Appendix 3.1: Impulse Response for a Special Case When aN = 0**
- **Matlab Session 3 Discrete-Time Signals and Systems**
- **3.M.1 Discrete-Time Functions and Stem Plots**
- **3.M.2 System Responses Through Filtering**
- **3.M.3 A Custom Filter Function**
- **3.M.4 Discrete-Time Convolution**
- **4 Continuous-Time System Analysis Using the Laplace Transform**
- **4.1 The Laplace Transform**
- **4.2 Some Properties of the Laplace Transform**
- **4.3 Solution of Differential and Integro-Differential Equations**
- **4.4 Analysis of Electrical Networks: The Transformed Network**
- **4.5 Block Diagrams**
- **4.6 System Realization**
- **4.7 Application to Feedback and Controls**
- **4.8 Frequency-Response of an LTIC System**
- **4.9 Bode Plots**
- **4.10 Filter Design by Placement of Poles and Zeros of H(s)**
- **4.11 The Bilateral Laplace Transform**
- **Matlab Session 4 Continuous-Time Filters**
- **4.M.1 Frequency Response and Polynomial Evaluation**
- **4.M.2 Design and Evaluation of a Simple RC Filter**
- **4.M.3 A Cascaded RC Filter and Polynomial Expansion**
- **4.M.4 Butterworth Filters and the FIND Command**
- **4.M.5 Butterworth Filter Realization Using Cascaded Second.Order Sections**
- **4.M.6 Chebyshev Filters**
- **5 Discrete-Time System Analysis Using the z-Transform**
- **5.1 The z-Transform**
- **5.2 Some Properties of the z-Transform**

- **5.3 z-Transform Solution of Linear Difference equations**
- **5.4 System Realization**
- **5.5 Frequency Response of Discrete-Time Systems**
- **5.6 Frequency Response from Pole-Zero Location**
- **5.7 Digital Processing of Analog Signals**
- **5.8 Connection Between the Laplace and the z-Transform**
- **5.9 The Bilateral z-Transform**
- **Matlab Session 5 Discrete-Time IIR Filters**
- **5.M.1 Frequency Response and Pole-Zero Plots**
- **5.M.2 Transformation Basics**
- **5.M.3 Transformation by First-Order Backward Difference**
- **5.M.4 Bilinear Transformation**
- **5.M.5 Bilinear Transformation with Prewarping**
- **5.M.6 Example: Butterworth Filter Transformation**
- **5.M.7 Problems Finding Polynomial Roots**
- **5.M.8 Improved Design Using Cascaded Second-Order Sections**
- **6 Continuous-Time Signal Analysis: The Fourier Series**
- **6.1 Periodic Signal Representation by Trigonometric Fourier Series**
- **6.2 Existence and Convergence of the Fourier Series**
- **6.3 Exponential Fourier Series**
- **6.4 LTIC System Response to Periodic Inputs**
- **6.5 Generalized Fourier Series: Signals as Vectors**
- **6.6 Numerical Computation of Dn**
- **Matlab Session 6 Fourier Series Applications**
- **6.M.1 Periodic Functions and the Gibbs Phenomenon**
- **6.M.2 Optimization and Phase Spectra**
- **7 Continuous-Time Signal Analysis: The Fourier Transform**
- **7.1 Aperiodic Signal Representation by Fourier Integral**
- **7.2 Transforms of Some Useful Functions**
- **7.3 Some Properties of the Fourier Transform**
- **7.4 Signal Transmission Through LTIC Systems**
- **7.5 Ideal and Practical Filters**
- **7.6 Signal Energy**
- **7.7 Application to Communications: Amplitude Modulation**
- **7.8 Data Truncation: Window Functions**
- **Matlab Session 7 Fourier Transform Topics**
- **7.M.1 The Sinc Function and the Scaling Property**
- **7.M.2 Parseval's Theorem and Essential Bandwidth**
- **7.M.3 Spectral Sampling**
- **7.M.4 Kaiser Window Functions**
- **8 Sampling: The Bridge from Continuous to Discrete**
- **8.1 The Sampling Theorem**
- **8.2 Signal Reconstruction**
- **8.3 Analog-to-Digital (A/D) Conversion**
- **8.4 Dual of Time-Sampling: The Spectral Sampling**

- **8.5 Numerical Computation of the Fourier Transform: The Discrete Fourier Transform (DFT)**
- **8.6 The Fast Fourier Transform (FFT)**
- **Matlab Session 8 The Discrete Fourier Transform**
- **8.M.1 Computing the Discrete Fourier Transform**
- **8.M.2 Improving the Picture with Zero-Padding**
- **8.M.3 Quantization**
- **9 Fourier Analysis of Discrete-Time Signals**
- **9.1 Discrete-Time Fourier Series (DTFS)**
- **9.2 Aperiodic Signal Representation by Fourier Integral**
- **9.3 Properties of DTFT**
- **9.4 LTI Discrete-Time System Analysis by DTFT**
- **9.5 DTFT Connection with the CTFT**
- **9.6 Generalization of the DTFT and the z-Transform**
- **Matlab Session 9 Working with the DTFS and the DTFT**
- **9.M.1 Computing the Discrete-Time Fourier Series**
- **9.M.2 Measuring Code Performance**
- **9.M.3 FIR Filter Design by Frequency Sampling**
- **10 State-Space Analysis**
- **10.1 Introduction**
- **10.2 A Systematic Procedure for Determining State Equations**
- **10.3 Solution of State Equations**
- **10.4 Linear Transformation of State Vectors**
- **10.5 Controllability and Observability**
- **10.6 State-Space Analysis of Discrete-Time Systems**
- **Matlab Session 10 Toolboxes and State-Space Analysis**
- **10.M.1 z-Transform Solutions to Discrete-Time State-Space Systems**
- **10.M.2 Transfer Functions from State-Space Representations**
- **10.M.3 Controllability and Observability of Discrete-Time Systems**
- **10.M.4 Matrix Exponentiation and the Matrix Exponential**
- **Index**