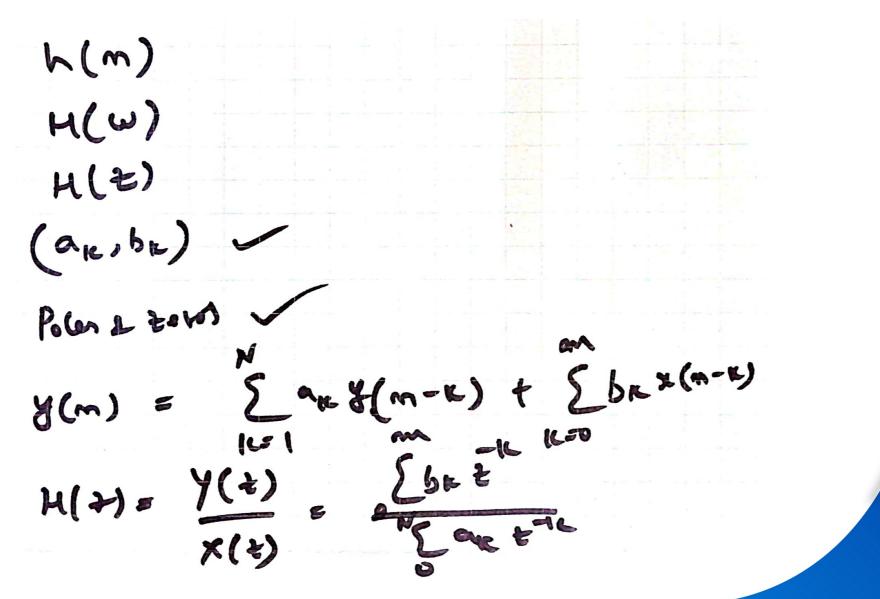
System Representations & Pole-Zero Representation

System Representations

- Time Domain Representation x(n), y(n), h(n)
- Frequency Domain Representation X(W), Y(W), H(W)
- Z-Transform Representation X(Z), Y(Z), H(Z)
- Difference Equation Representation (a_k, b_k)
- Pole Zero Representation H(Z) = Y(Z)/X(Z)

System Representations



Z-Transform & Difference Equations

 $X(t) = \begin{cases} x(m) \\ y = -\infty \end{cases} \xrightarrow{(m) \\ y = -\infty \end{cases} \xrightarrow{(m) \\ y = -\infty \end{cases} \xrightarrow{(m) \\ z = \\ y = -\infty \end{cases} \xrightarrow{(m) \\ z = \\ y = -\infty$ 2- Trounform X(2) | = DFT[I(m)], t=e X(m)=X(m)=X(4)R=1 2(1) $y(m) = a_1 y(m-1) + a_2 y(m-2) + - - + a_1 x y(m-n)$ + bo $x(m) + g_1 x(m-1) + h_1 x(m-2) = -.. + G_m \{x(m-m)\}$ $= \gamma(z) \left[a_{1}z^{\dagger} + a_{2}z^{\dagger} + \cdots + a_{N}z^{N} \right] + \gamma(z) \left[b_{0}z^{\dagger} + b_{1}z^{\dagger} + \cdots + b_{m}z^{m} \right]$ $H(t) = \frac{Y(t)}{X(t)} = \frac{\sum b_k t^k}{k = 0} / 1 - \sum a_k t^k = \frac{\sum b_k t^k}{N - \sum a_k t^k}$

