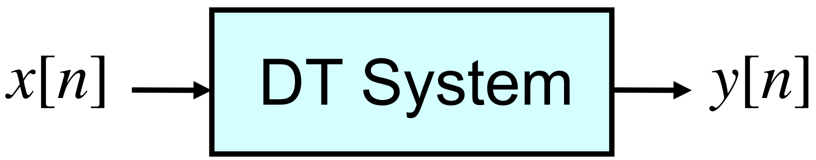
ELEN E4810: Digital Signal Processing
Topic 2: Time domain

1. Discrete-time systems
2. Convolution
3. Linear Constant-Coefficient Difference Equations (LCCDEs)
4. Correlation

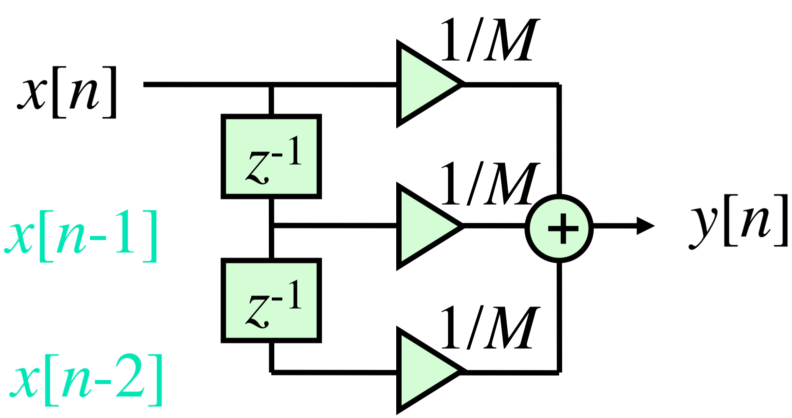
1. Discrete-time systems

- A **system** converts input to output:



$$\{y[n]\} = f(\{x[n]\}) \;\forall n$$

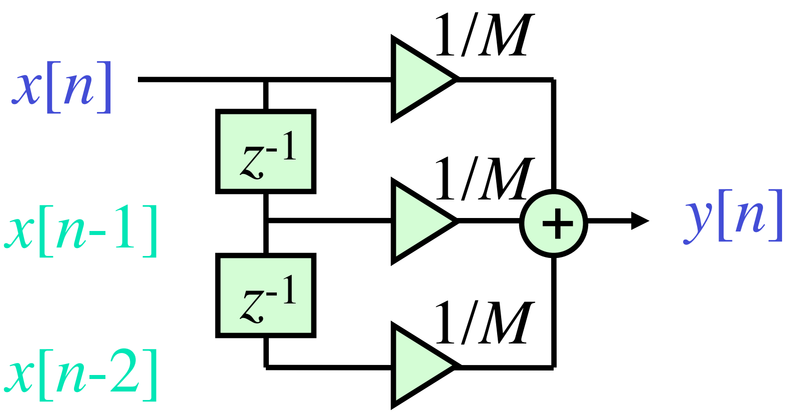
- E.g. Moving Average (MA):

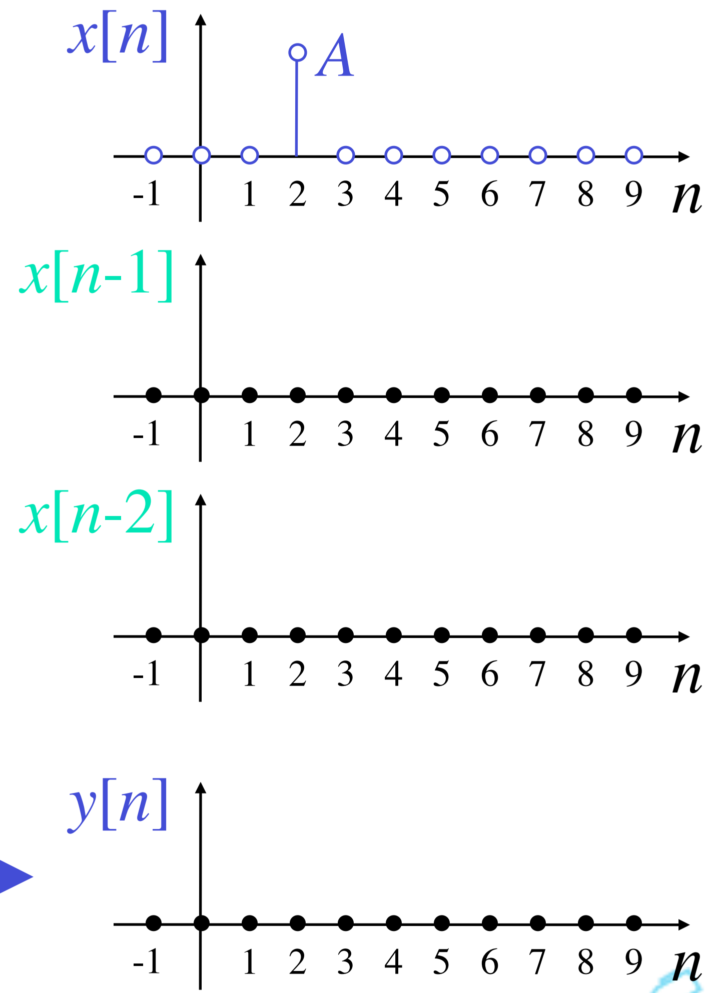


$$y[n] = \frac{1}{M}\sum_{k=0}^{M-1} x[n-k]$$

$$(M = 3)$$

Moving Average (MA)





$$y[n] = \frac{1}{M} \sum_{k=0}^{M-1} x[n-k] \rightarrow$$

MA Smoother

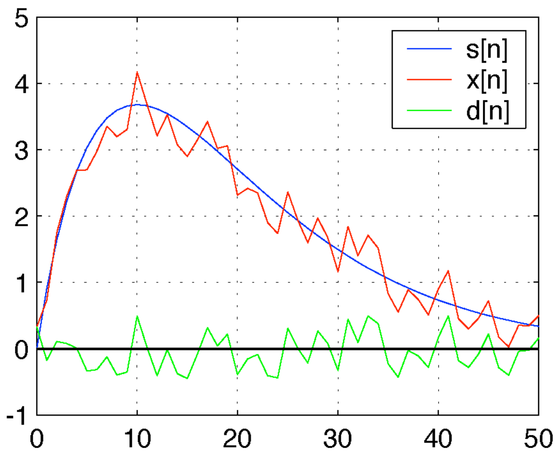
- MA smoothes out rapid variations (e.g. "12 month moving average")
- e.g.

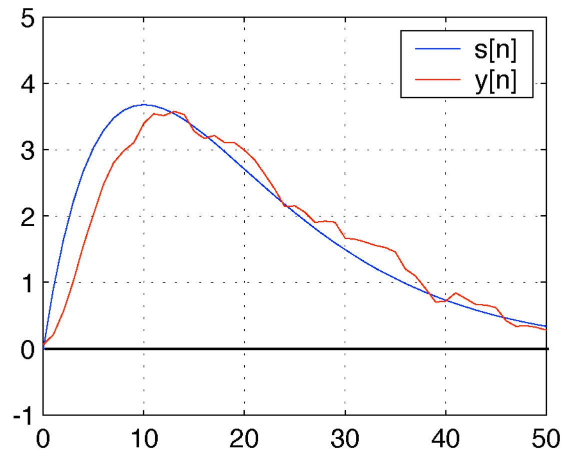
signal noise

$$x[n] = s[n] + d[n]$$

$$y[n] = \frac{1}{5}\sum_{k=0}^{4} x[n-k]$$

5-pt moving average





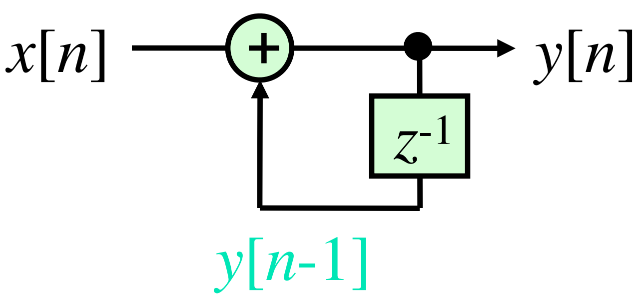
Accumulator

- Output accumulates all past inputs:

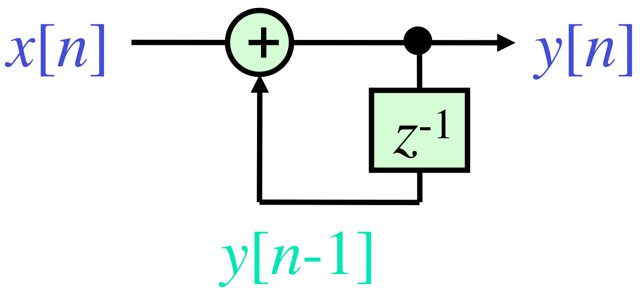
$$y[n] = \sum_{\ell=-\infty}^{n} x[\ell]$$

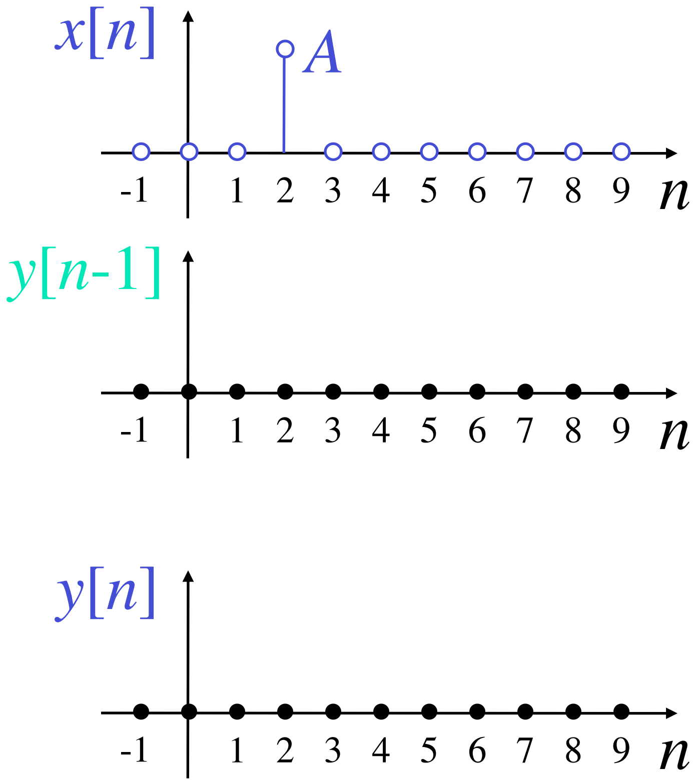
$$= \sum_{\ell=-\infty}^{n-1} x[\ell] + x[n]$$

$$= y[n-1] + x[n]$$



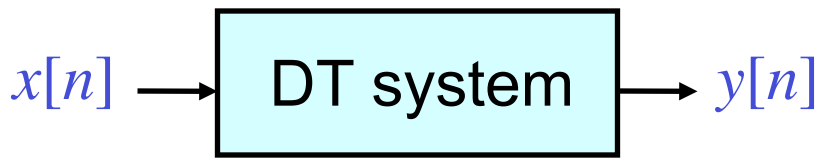
Accumulator





Classes of DT systems

- **Linear** systems obey superposition:



  - if input $x_1[n] \rightarrow$ output $y_1[n]$, $x_2 \rightarrow y_2$ ...
  - given a linear combination
    of inputs: $x[n] = \alpha\, x_1[n] + \beta\, x_2[n]$
  - then output $y[n] = \alpha\, y_1[n] + \beta\, y_2[n]$
    for *all* α, β, x_1, x_2

    i.e. same linear combination of outputs

Linearity: Example 1

- Accumulator: $y[n] = \sum_{\ell=-\infty}^{n} x[\ell]$

$$\boxed{x[n] = \alpha \cdot x_1[n] + \beta \cdot x_2[n]}$$

$$\rightarrow \quad y[n] = \sum_{\ell=-\infty}^{n} (\alpha x_1[\ell] + \beta x_2[\ell])$$

$$= \sum (\alpha x_1[\ell]) + \sum (\beta x_2[\ell])$$

$$= \alpha \sum x_1[\ell] + \beta \sum x_2[\ell]$$

$$\boxed{= \alpha \cdot y_1[n] + \beta \cdot y_2[n]}$$

✓ Linear

Linearity Example 2:

- "Teager Energy operator":

$$y[n] = x^2[n] - x[n-1] \cdot x[n+1]$$

$$x[n] = \alpha \cdot x_1[n] + \beta \cdot x_2[n]$$

$$\rightarrow y[n] = (\alpha x_1[n] + \beta x_2[n])^2$$
$$-(\alpha x_1[n-1] + \beta x_2[n-1])$$
$$\cdot(\alpha x_1[n+1] + \beta x_2[n+1])$$
$$\neq \alpha \cdot y_1[n] + \beta \cdot y_2[n]$$

✗ ***Nonlinear***

Linearity Example 3:

- 'Offset' accumulator: $$y[n] = C + \sum_{\ell=-\infty}^{n} x[\ell]$$

$$\Rightarrow y_1[n] = C + \sum_{\ell=-\infty}^{n} x_1[\ell]$$

but $$y[n] = C + \sum_{\ell=-\infty}^{n} \left(\alpha x_1[\ell] + \beta x_2[\ell]\right)$$

$$\neq \alpha y_1[n] + \beta y_2[n]$$ ✗ ***Nonlinear***

.. unless $C = 0$

Property: Shift (time) invariance

- **Time-shift** of input
  causes same shift in output
- i.e. if $x_1[n] \rightarrow y_1[n]$
  then $x[n] = x_1[n - n_0]$
  $\Rightarrow y[n] = y_1[n - n_0]$
- i.e. process doesn't depend on absolute value of n

Shift-invariance counterexample

- Upsampler: $x[n] \longrightarrow \boxed{\uparrow L} \longrightarrow y[n]$

$$y[n] = \begin{cases} x[n/L] & n = 0, \pm L, \pm 2L, \ldots \\ 0 & \text{otherwise} \end{cases}$$

$$y_1[n] = x_1[n/L] \quad (n = r \cdot L)$$

$$x[n] = x_1[n - n_0]$$

$$\Rightarrow y[n] = x[n/L] = x_1[n/L - n_0]$$

Not shift invariant

$$= x_1\left[\frac{n - L \cdot n_0}{L}\right] = y_1[n - L \cdot n_0] \neq y_1[n - n_0]$$

Another counterexample

$$y[n] = n \cdot x[n]$$ *scaling by time index*

- Hence $y_1[n-n_0] = (n-n_0) \cdot x_1[n-n_0]$
- If $x[n] = x_1[n-n_0]$
  then $y[n] = n \cdot x_1[n-n_0]$

$\neq$

- Not shift invariant
  - parameters depend on n

Linear Shift Invariant (LSI)

- Systems which are both linear and shift invariant are easily manipulated mathematically
- This is still a wide and useful class of systems
- If discrete index corresponds to time, called Linear Time Invariant (LTI)

Causality

- If output depends only on past and current inputs (not future), system is called **causal**
- Formally, if $x_1[n] \rightarrow y_1[n]$ & $x_2[n] \rightarrow y_2[n]$

Causal $\rightarrow$

$$x_1[n] = x_2[n] \quad \forall n < N$$
$$\Leftrightarrow y_1[n] = y_2[n] \quad \forall n < N$$

Causality example

- Moving average: $y[n] = \frac{1}{M}\sum_{k=0}^{M-1} x[n-k]$

  $y[n]$ depends on $x[n\text{-}k]$, $k \geq 0$ → causal
- 'Centered' moving average

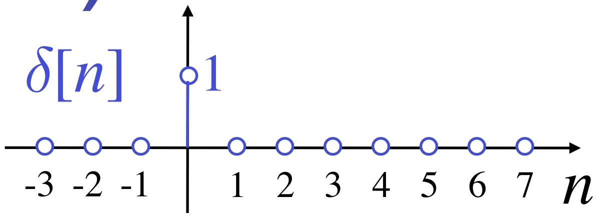
$$y_c[n] = y[n + (M-1)/2]$$

$$= \frac{1}{M}\left(x[n] + \sum_{k=1}^{(M-1)/2} x[n-k] + x[n+k]\right)$$

- .. looks forward in time → noncausal
- .. Can make causal by delaying

Impulse response (IR)

- Impulse $\delta[n] = \begin{cases} 1, & n = 0 \\ 0, & n \neq 0 \end{cases}$



  (unit sample sequence)

- Given a system: $x[n] \rightarrow$ DT system $\rightarrow y[n]$

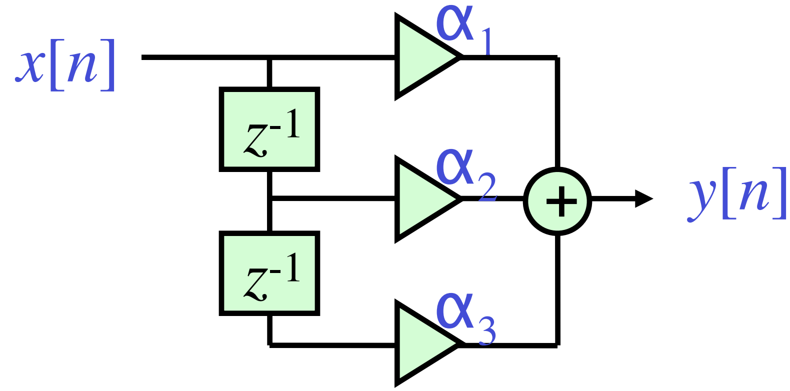
  if $x[n] = \delta[n]$ then $y[n] \triangleq h[n]$

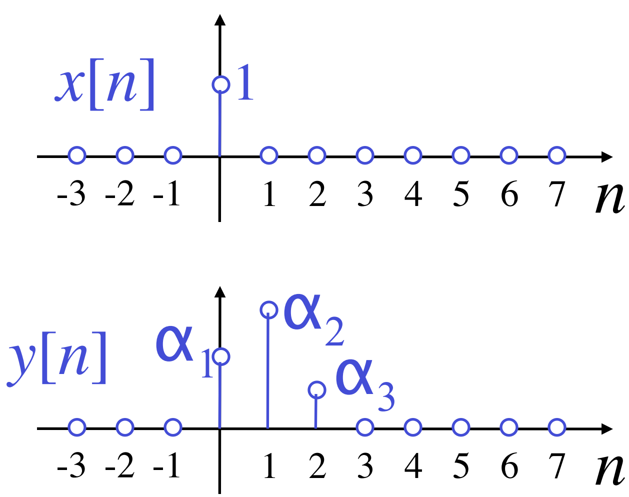
  "impulse response"

- LSI system completely specified by $h[n]$

Impulse response example

- Simple system:





$x[n] = \delta[n]$ impulse

$\downarrow$

$y[n] = h[n]$ impulse response

2. Convolution

- Impulse response: $\delta[n] \longrightarrow \boxed{\text{LSI}} \longrightarrow h[n]$
- Shift invariance: $\delta[n-n_0] \longrightarrow \boxed{\text{LSI}} \longrightarrow h[n-n_0]$
- + Linearity: $\alpha \cdot \delta[n-k] + \beta \cdot \delta[n-l] \longrightarrow \boxed{\text{LSI}} \longrightarrow \alpha \cdot h[n-k] + \beta \cdot h[n-l]$
- Can express any sequence with δs:

$$x[n] = x[0]\delta[n] + x[1]\delta[n-1] + x[2]\delta[n-2]..$$

Convolution sum

- Hence, since $x[n] = \sum_{k=-\infty}^{\infty} x[k]\delta[n-k]$
- For LSI, $\boxed{y[n] = \sum_{k=-\infty}^{\infty} x[k]h[n-k]}$ **Convolution sum**

  written as $y[n] = x[n] \circledast h[n]$
- Summation is symmetric in x and h
  i.e. $l = n - k \rightarrow$

  $$x[n] \circledast h[n] = \sum_{l=-\infty}^{\infty} x[n-l]h[l] = h[n] \circledast x[n]$$

Convolution properties

- **LSI System output $y[n]$ = input $x[n]$ convolved with impulse response $h[n]$ → $h[n]$ completely describes system**
- Commutative: $x[n] \circledast h[n] = h[n] \circledast x[n]$
- Associative:

$$(x[n] \circledast h[n]) \circledast y[n] = x[n] \circledast (h[n] \circledast y[n])$$

- Distributive:

$$h[n] \circledast (x[n] + y[n]) = h[n] \circledast x[n] + h[n] \circledast y[n]$$

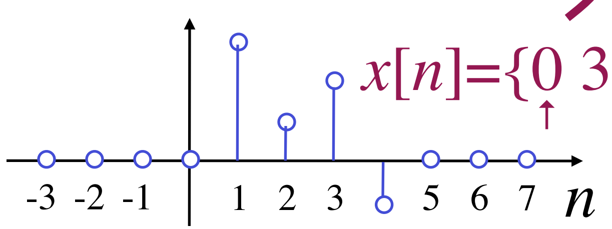
Interpreting convolution

- Passing a signal through a (LSI) system is equivalent to convolving it with the system's impulse response

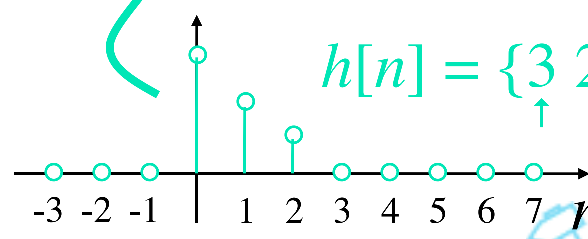
$$x[n] \longrightarrow \boxed{h[n]} \longrightarrow y[n] = x[n] \circledast h[n]$$

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

$x[n]=\{0\ 3\ 1\ 2\ -1\}$



$h[n] = \{3\ 2\ 1\}$

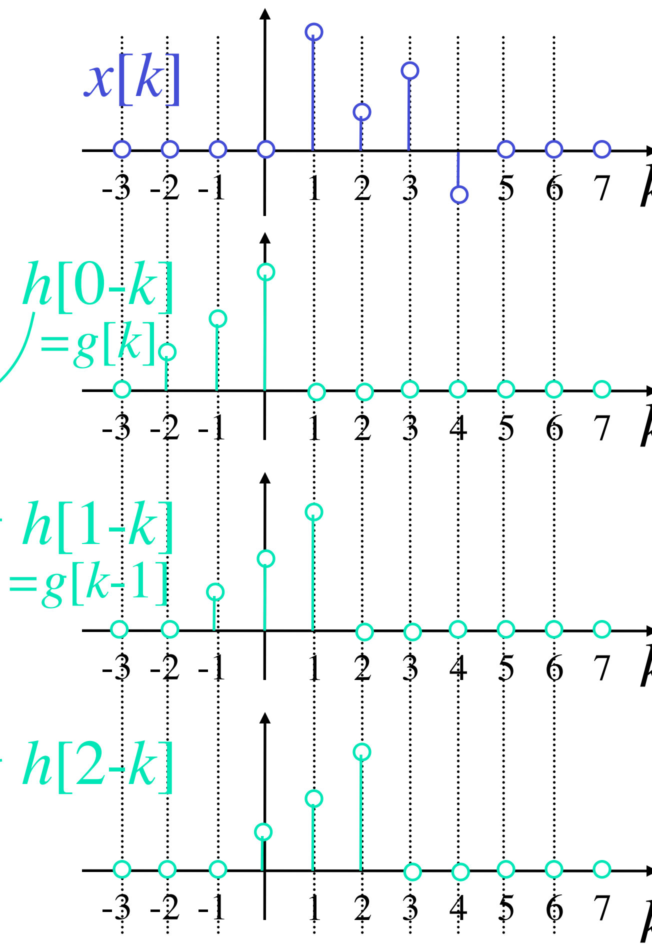


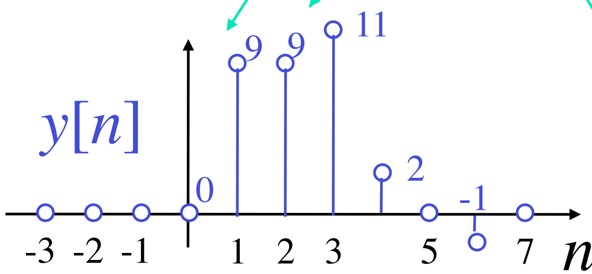
Convolution interpretation 1

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

call $h[-n] = g[n]$

- Time-reverse h, shift by n, take inner product against fixed x

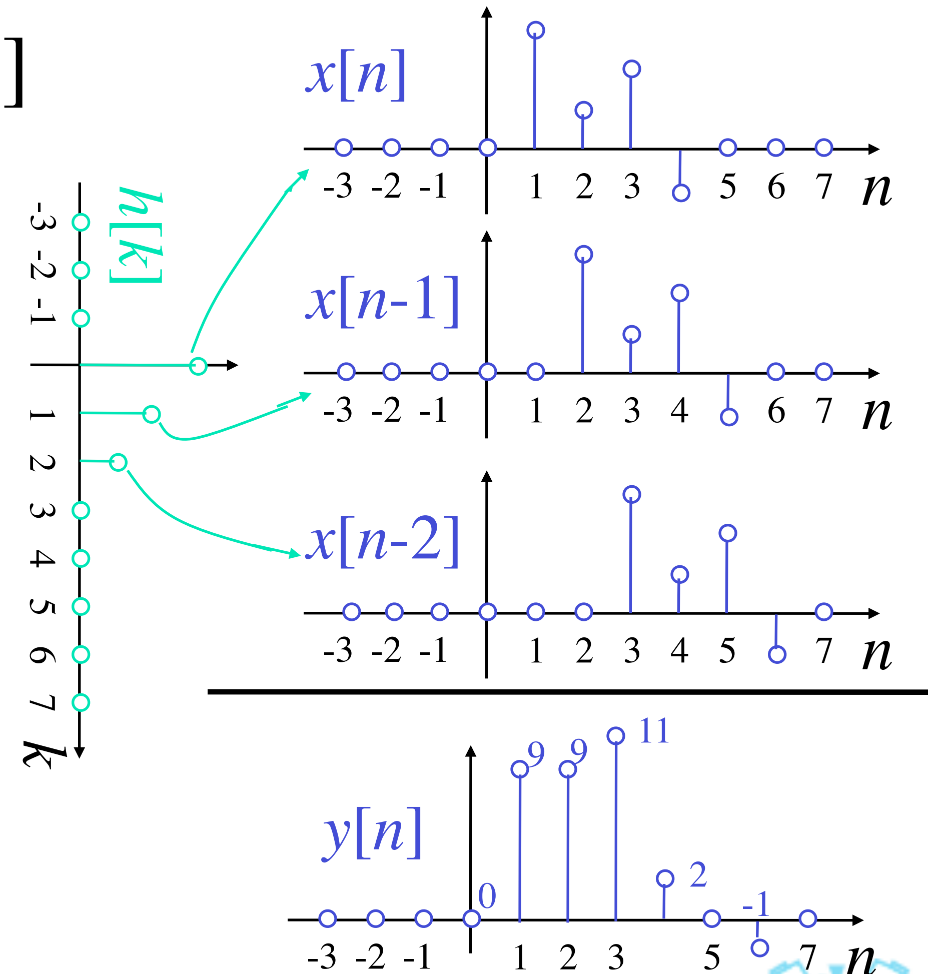




Convolution interpretation 2

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

- Shifted x's weighted by points in h
- Conversely, weighted, delayed versions of h ...



Matrix interpretation

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

$$\begin{bmatrix} y[0] \\ y[1] \\ y[2] \\ \cdots \end{bmatrix} = \begin{bmatrix} x[0] & x[-1] & x[-2] \\ x[1] & x[0] & x[-1] \\ x[2] & x[1] & x[0] \\ \cdots & \cdots & \cdots \end{bmatrix} \begin{bmatrix} h[0] \\ h[1] \\ h[2] \end{bmatrix}$$

- Diagonals in $\mathbf{X}$ matrix are equal

Convolution notes

- Total nonzero length of convolving N and M point sequences is $N+M-1$
- Adding the indices of the terms within the summation gives n :

$$y[n] = \sum_{k=-\infty}^{\infty} h[k]x[n-k] \qquad k + (n-k) = n$$

i.e. summation indices move in opposite senses

Convolution in MATLAB

- The M-file `conv` implements the convolution sum of two finite-length sequences
- If $a = [0 \quad 3 \quad 1 \quad 2 \quad -1]$

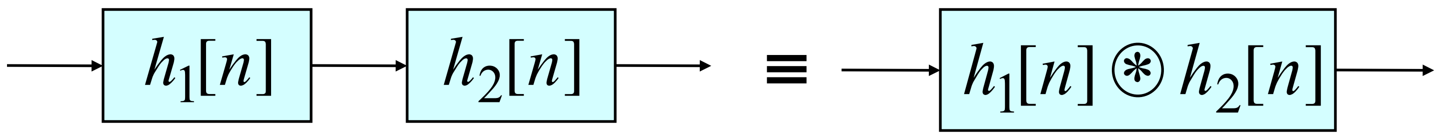
  $b = [3 \quad 2 \quad 1]$

  then `conv(a,b)` yields

  $[0 \quad 9 \quad 9 \quad 11 \quad 2 \quad 0 \quad -1]$

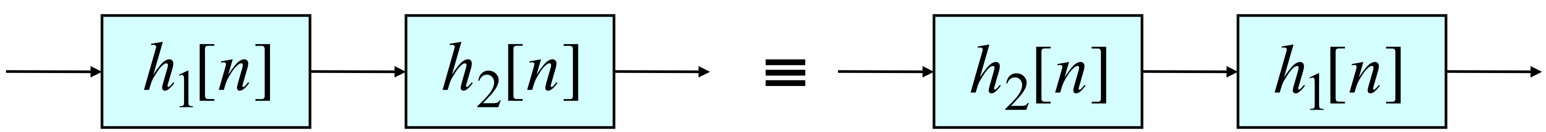
Connected systems

- **Cascade** connection:



Impulse response $h[n]$ of the cascade of two systems with impulse responses $h_1[n]$ and $h_2[n]$ is $h[n] = h_1[n] \circledast h_2[n]$

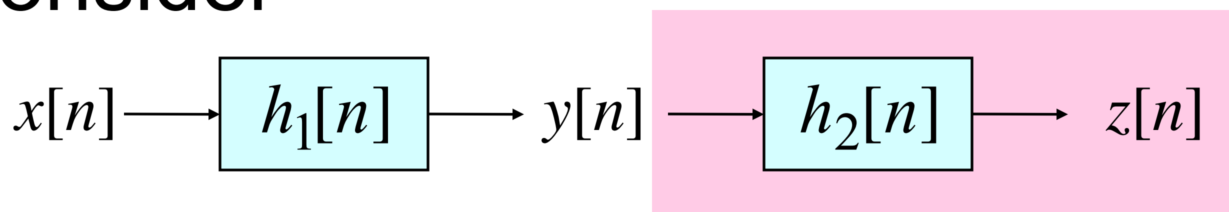
- By commutativity,



Inverse systems

- $\delta[n]$ is identity for convolution

  i.e. $x[n] \circledast \delta[n] = x[n]$
- Consider



$$z[n] = h_2[n] \circledast y[n] = h_2[n] \circledast h_1[n] \circledast x[n]$$

$$= x[n] \quad \textbf{if} \quad h_2[n] \circledast h_1[n] = \delta[n]$$

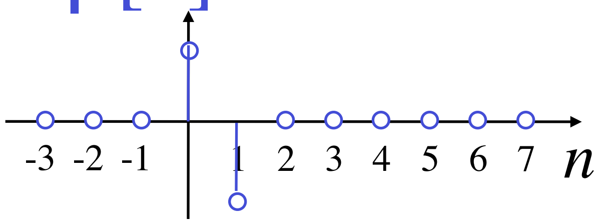
- $h_2[n]$ is the **inverse system** of $h_1[n]$

Inverse systems

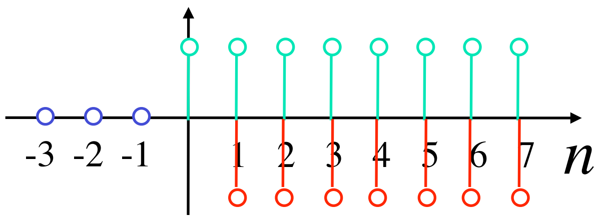
- Use inverse system to recover input $x[n]$ from output $y[n]$ (e.g. to undo effects of transmission channel)
- Only sometimes possible - e.g. cannot 'invert' $h_1[n] = 0$
- In general, attempt to solve $h_2[n] \circledast h_1[n] = \delta[n]$

Inverse system example

- Accumulator:
  Impulse response $h_1[n] = \mu[n]$

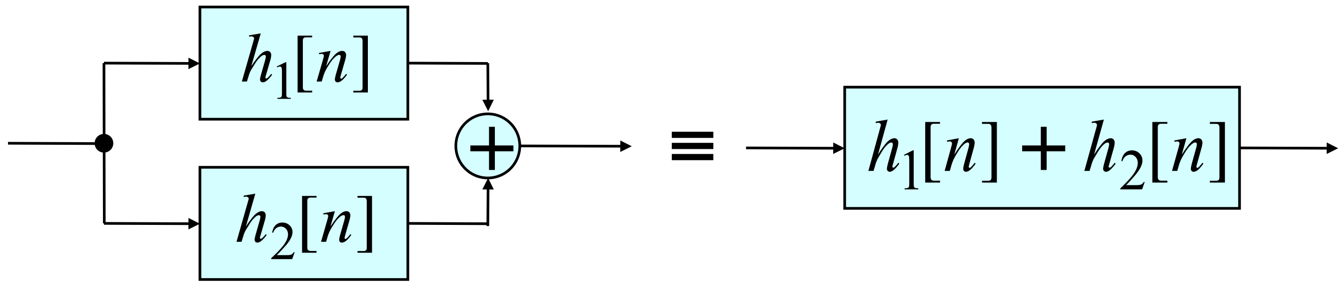


- 'Backwards difference'
  $$h_2[n] = \delta[n] - \delta[n-1]$$
  .. has desired property:
  $$\mu[n] - \mu[n-1] = \delta[n]$$



- Thus, 'backwards difference' is inverse system of accumulator.

Parallel connection



- Impulse response of two parallel systems added together is:

$$h[n] = h_1[n] + h_2[n]$$

3. Linear Constant-Coefficient Difference Equation (LCCDE)

- General spec. of DT, LSI, finite-dim sys:

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

  - defined by $\{d_k\},\{p_k\}$
  - **order** = $\max(N,M)$

- Rearrange for $y[n]$ in causal form:

$$y[n] = -\sum_{k=1}^{N} \frac{d_k}{d_0} y[n-k] + \sum_{k=0}^{M} \frac{p_k}{d_0} x[n-k]$$

- WLOG, always have $d_0 = 1$

Solving LCCDEs

- "Total solution"

$$y[n] = \underbrace{y_c[n]}_{\text{Complementary Solution}} + \underbrace{y_p[n]}_{\text{Particular Solution}}$$

Complementary Solution

satisfies $\displaystyle\sum_{k=0}^{N} d_k y[n-k] = 0$

Particular Solution

for given forcing function

$x[n]$

Complementary Solution

- General form of unforced oscillation i.e. system's 'natural modes'
- Assume y_c has form $y_c[n] = \lambda^n$

$$\Rightarrow \sum_{k=0}^{N} d_k \lambda^{n-k} = 0$$

$$\Rightarrow \lambda^{n-N}\left(d_0\lambda^N + d_1\lambda^{N-1} + \ldots + d_{N-1}\lambda + d_N\right) = 0$$

$$\Rightarrow \sum_{k=0}^{N} d_k \lambda^{N-k} = 0$$

Characteristic polynomial of system - depends only on $\{d_k\}$

Complementary Solution

- $\sum_{k=0}^{N} d_k \lambda^{N-k} = 0$ factors into roots λ_i, i.e.
$$(\lambda - \lambda_1)(\lambda - \lambda_2)\ldots = 0$$
- Each/any λ_i satisfies eqn.
- Thus, complementary solution:
$$y_c[n] = \alpha_1 \lambda_1{}^n + \alpha_2 \lambda_2{}^n + \alpha_3 \lambda_3{}^n + \ldots$$
Any linear combination will work
→ α_is are free to match initial conditions

Complementary Solution

- Repeated roots in chr. poly:

$$(\lambda-\lambda_1)^{L}(\lambda-\lambda_2)\ldots=0$$
$$\Rightarrow y_c[n]=\alpha_1\lambda_1^{\,n}+\alpha_2 n\lambda_1^{\,n}+\alpha_3 n^2\lambda_1^{\,n}$$
$$+\ldots+\alpha_L n^{L-1}\lambda_1^{\,n}+\ldots$$

- Complex λ_is → sinusoidal $y_c[n]=\alpha_i\lambda_i^{\,n}$

Particular Solution

- Recall: Total solution $y[n] = y_c[n] + \boxed{y_p[n]}$
- Particular solution reflects input
- 'Modes' usually decay away for large n leaving just $y_p[n]$
- Assume 'form' of $x[n]$, scaled by β:
  e.g. $x[n]$ constant → $y_p[n] = \beta$
  $x[n] = \lambda_0^n \rightarrow y_p[n] = \beta \cdot \lambda_0^n \quad (\lambda_0 \notin \lambda_i)$
  or $= \beta\, n^{L} \lambda_0^n \quad (\lambda_0 \in \lambda_i)$

LCCDE example

$$y[n] + y[n-1] - 6y[n-2] = x[n]$$

- Need input: $x[n] = 8\mu[n]$
- Need initial conditions:
  $y[-1] = 1,\ y[-2] = -1$

LCCDE example

- Complementary solution:

$$y[n]+y[n-1]-6y[n-2]=0; \quad y[n]=\lambda^n$$

$$\Rightarrow \lambda^{n-2}\left(\lambda^2+\lambda-6\right)=0$$

$$\Rightarrow (\lambda+3)(\lambda-2)=0 \rightarrow \text{roots } \lambda_1 = -3,\ \lambda_2 = 2$$

$$\Rightarrow y_c[n]=\alpha_1(-3)^n+\alpha_2(2)^n$$

- α_1, α_2 are unknown at this point

LCCDE example

- Particular solution:
- Input $x[n]$ is constant $= 8\mu[n]$

  assume $y_p[n] = \beta$, substitute in:

  $$y[n] + y[n-1] - 6y[n-2] = x[n] \qquad (\text{‘large’ } n)$$

  $$\Rightarrow \beta + \beta - 6\beta = 8\mu[n]$$

  $$\Rightarrow -4\beta = 8 \Rightarrow \beta = -2$$

LCCDE example

- Total solution $y[n] = y_c[n] + y_p[n]$

$$= \alpha_1(-3)^n + \alpha_2(2)^n + \beta$$

- Solve for unknown α_is by substituting *initial conditions* into DE at $n = 0, 1, ...$

$$y[n] + y[n-1] - 6y[n-2] = x[n]$$

from ICs

- $n = 0$ $\quad y[0] + y[-1] - 6y[-2] = x[0]$

$$\Rightarrow \alpha_1 + \alpha_2 + \beta + 1 + 6 = 8$$

$$\Rightarrow \alpha_1 + \alpha_2 = 3$$

LCCDE example

- $n = 1$ $\quad y[1] + y[0] - 6y[-1] = x[1]$

  $\Rightarrow \alpha_1(-3) + \alpha_2(2) + \beta + \alpha_1 + \alpha_2 + \beta - 6 = 8$

  $\Rightarrow -2\alpha_1 + 3\alpha_2 = 18$
- solve: $\alpha_1 = -1.8$, $\alpha_2 = 4.8$
- Hence, system output:

  $y[n] = -1.8(-3)^n + 4.8(2)^n - 2 \quad n \geq 0$
- *Don't* find α_is by solving with ICs at $n = -1,-2$

  *(ICs may not reflect natural modes; Mitra3 ex 2.37-8 (4.22-3) is **wrong**)*

LCCDE solving summary

- Difference Equation (DE):
  $Ay[n] + By[n\text{-}1] + \ldots = Cx[n] + Dx[n\text{-}1] + \ldots$
  Initial Conditions (ICs): $y[\text{-}1] = \ldots$
- DE RHS = 0 with $y[n]{=}\lambda^n \rightarrow$ roots $\{\lambda_i\}$
  gives complementary soln $y_c[n] = \sum \alpha_i \lambda_i^{\,n}$
- Particular soln: $y_p[n] \sim x[n]$
  solve for $\beta\lambda_0^{\,n}$ "at large n"
- α_is by substituting DE at $n = 0, 1, \ldots$
  ICs for $y[\text{-}1], y[\text{-}2]$; $y_t{=}y_c{+}y_p$ for $y[0], y[1]$

LCCDEs: zero input/zero state

- Alternative approach to solving LCCDEs is to solve two subproblems:
  - $y_{zi}[n]$, response with zero input (just ICs)
  - $y_{zs}[n]$, response with zero state (just $x[n]$)
- Because of linearity, $y[n] = y_{zi}[n] + y_{zs}[n]$
- Both subproblems are 'fully realized'
- But, have to solve for α_is twice (then sum them)

Impulse response of LCCDEs

- Impulse response: $\delta[n] \longrightarrow \boxed{\text{LCCDE}} \longrightarrow h[n]$

  i.e. solve with $x[n] = \delta[n] \rightarrow y[n] = h[n]$ (zero ICs)

- With $x[n] = \delta[n]$, 'form' of $y_p[n] = \beta\delta[n]$

  → solve $y[n]$ for $n = 0, 1, 2...$ to find α_is

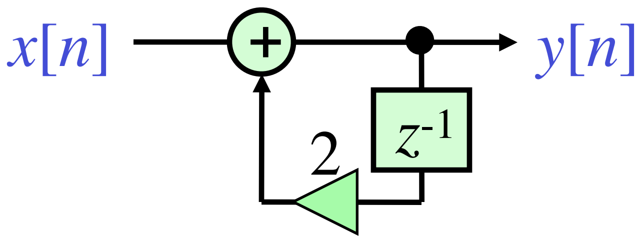
LCCDE IR example

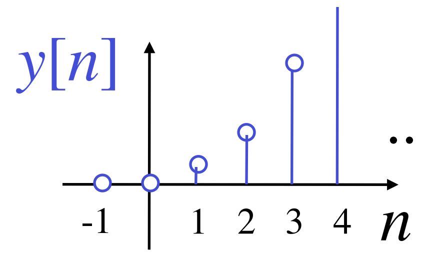
- e.g. $y[n] + y[n-1] - 6y[n-2] = x[n]$
  (from before); $x[n] = \delta[n]$; $y[n] = 0$ for $n<0$
- $y_c[n] = \alpha_1(-3)^n + \alpha_2(2)^n$ $\quad y_p[n] = \beta\delta[n]$
- $n = 0$: $y[0] + \cancel{y[-1]} - 6\cancel{y[-2]} = \cancel{x[0]} \; 1$
  $\Rightarrow \alpha_1 + \alpha_2 + \beta = 1$
- $n = 1$: $\alpha_1(-3) + \alpha_2(2) + 1 = 0$
- $n = 2$: $\alpha_1(9) + \alpha_2(4) - 1 - 6 = 0$
  $\Rightarrow \alpha_1 = 0.6,\ \alpha_2 = 0.4,\ \beta = 0$
- thus $h[n] = 0.6(-3)^n + 0.4(2)^n$ $\quad n \geq 0$

Infinite length

System property: **Stability**

- Certain systems can be unstable e.g.





Output grows without limit in some conditions

Stability

- Several definitions for stability; we use **Bounded-input, bounded-output (BIBO) stable**
- For *every* bounded input $|x[n]| < B_x \quad \forall n$ output is also subject to a finite bound,

$$|y[n]| < B_y \quad \forall n$$

Stability example

- MA filter: $y[n] = \frac{1}{M}\sum_{k=0}^{M-1} x[n-k]$

$$|y[n]| = \left|\frac{1}{M}\sum_{k=0}^{M-1} x[n-k]\right|$$

$$\leq \frac{1}{M}\sum_{k=0}^{M-1} |x[n-k]|$$

$$\leq \frac{1}{M} M \cdot B_x \leq B_y$$

→ **BIBO Stable**

Stability & LCCDEs

- LCCDE output is of form:

$$y[n] = \alpha_1 \lambda_1{}^n + \alpha_2 \lambda_2{}^n + \ldots + \beta \lambda_0{}^n + \ldots$$

- αs and βs depend on input & ICs, *but* to be bounded for any input we need $|\lambda| < 1$

4. Correlation

- Correlation ~ identifies similarity between sequences:

Cross correlation of x against y

$$r_{xy}[\ell] = \sum_{n=-\infty}^{\infty} x[n]y[n-\ell]$$

"lag"

- Note: $r_{yx}[\ell] = \sum_{n=-\infty}^{\infty} y[n]x[n-\ell]$

call $m = n - \ell$

$$= \sum_{m=-\infty}^{\infty} y[m+\ell]x[m] = r_{xy}[-\ell]$$

Correlation and convolution

- Correlation: $$r_{xy}[n] = \sum_{k=-\infty}^{\infty} x[k]y[k-n]$$
- Convolution: $$x[n] \circledast y[n] = \sum_{k=-\infty}^{\infty} x[k]y[n-k]$$
- Hence: $$r_{xy}[n] = x[n] \circledast y[-n]$$

Correlation may be calculated by convolving with time-reversed sequence

Autocorrelation

- Autocorrelation (AC) is correlation of signal with itself:

$$r_{xx}[\ell] = \sum_{n=-\infty}^{\infty} x[n]x[n-\ell] = r_{xx}[-\ell]$$

- Note: $r_{xx}[0] = \sum_{n=-\infty}^{\infty} x^2[n] = \varepsilon_x$

Energy of sequence $x[n]$

Correlation maxima

- Note: $r_{xx}[\ell] \leq r_{xx}[0] \Rightarrow \left|\frac{r_{xx}[\ell]}{r_{xx}[0]}\right| \leq 1$
- Similarly: $r_{xy}[\ell] \leq \sqrt{\varepsilon_x \varepsilon_y} \Rightarrow \frac{r_{xy}[\ell]}{\sqrt{r_{xx}[0] r_{yy}[0]}} \leq 1$
- From geometry,

$$\langle \mathbf{xy} \rangle = \sum_i x_i y_i = \underbrace{|\mathbf{x}|}_{\sqrt{\sum x_i^2}} |\mathbf{y}| \cos\theta$$

angle between x and y

- when $\mathbf{x}//\mathbf{y}$, $\cos\theta = 1$, else $\cos\theta < 1$

AC of a periodic sequence

- Sequence of period N: $\tilde{x}[n] = \tilde{x}[n+N]$
- Calculate AC over a finite window:

$$r_{\tilde{x}\tilde{x}}[\ell] = \frac{1}{2M+1} \sum_{n=-M}^{M} \tilde{x}[n]\tilde{x}[n-\ell]$$

$$= \frac{1}{N} \sum_{n=0}^{N-1} \tilde{x}[n]\tilde{x}[n-\ell] \qquad \text{if } M >> N$$

AC of a periodic sequence

$$r_{\tilde{x}\tilde{x}}[0] = \frac{1}{N}\sum_{n=0}^{N-1} \tilde{x}^2[n] = P_{\tilde{x}}$$

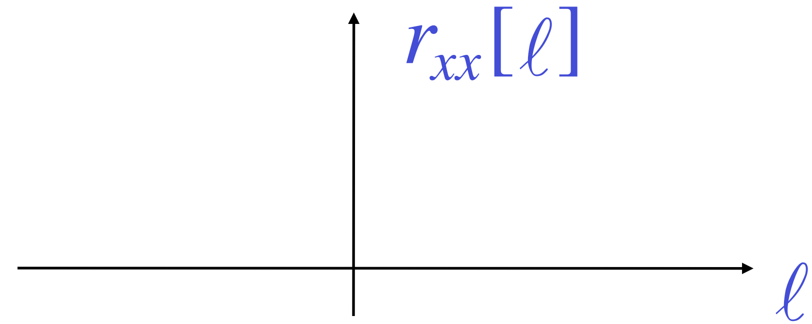
Average energy per sample or **Power** of x

$$r_{\tilde{x}\tilde{x}}[\ell + N] = \frac{1}{N}\sum_{n=0}^{N-1} \tilde{x}[n]\tilde{x}[n-\ell-N] = r_{\tilde{x}\tilde{x}}[\ell]$$

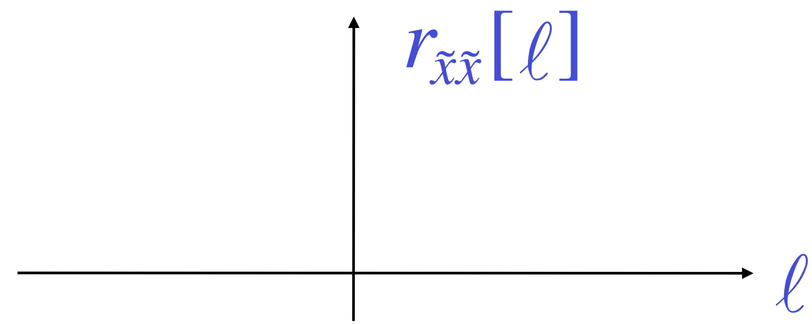
- i.e AC of periodic sequence is periodic

What correlations look like

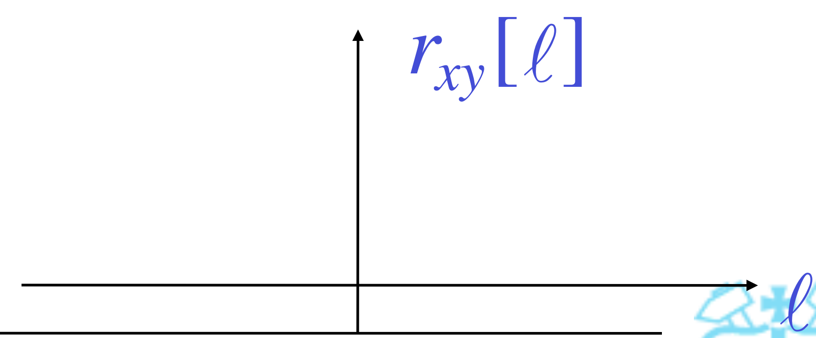
- AC of any $x[n]$



- AC of periodic

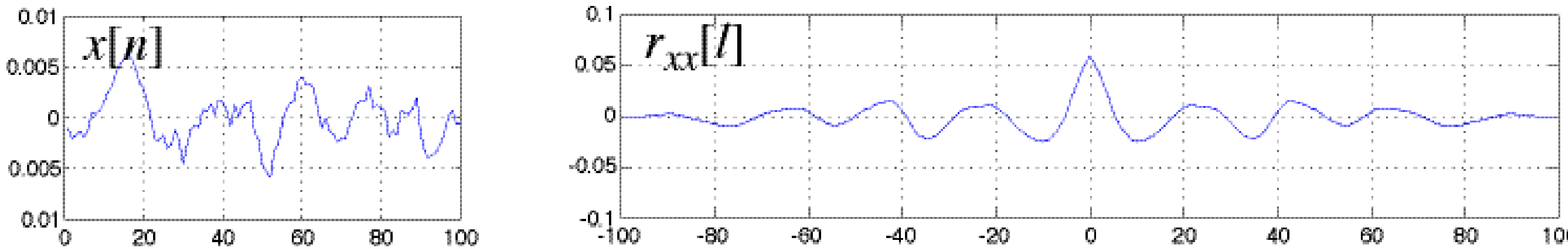


- Cross correlation

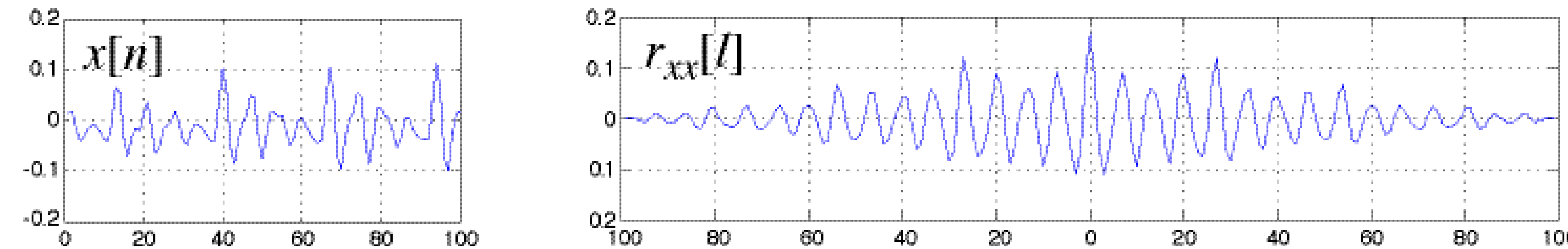


What correlation looks like

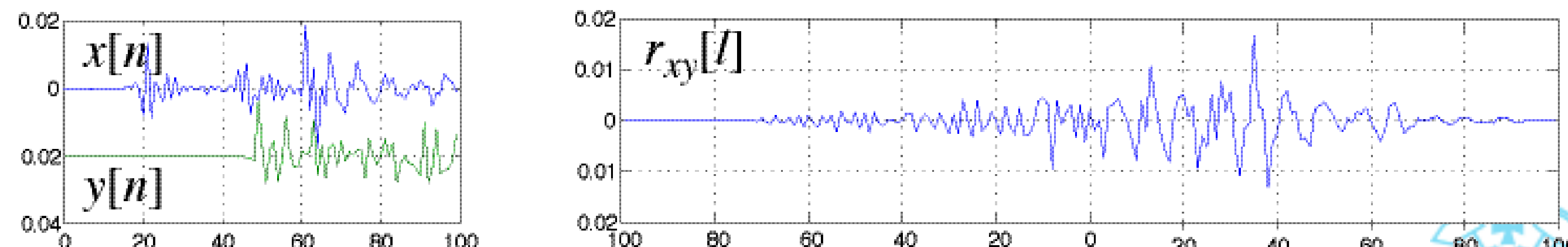
Autocorrelation of generic signal



Autocorrelation of near-periodic signal

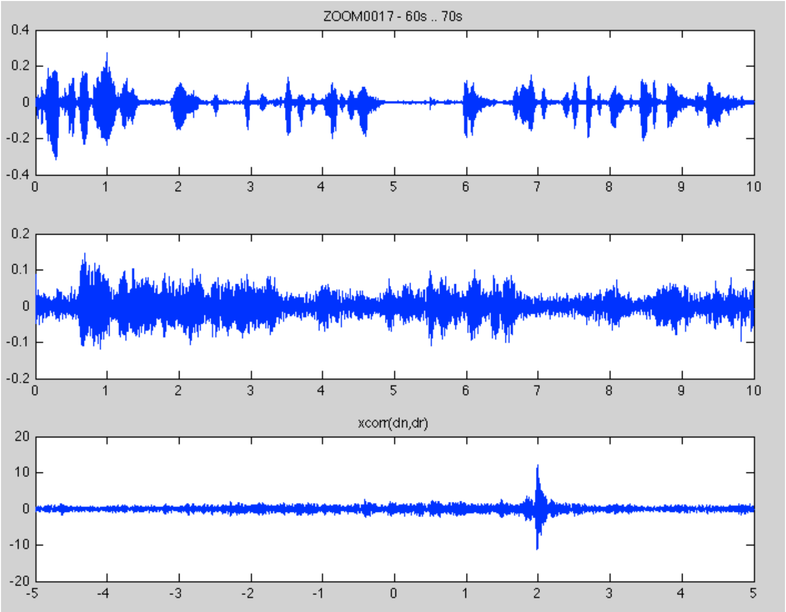


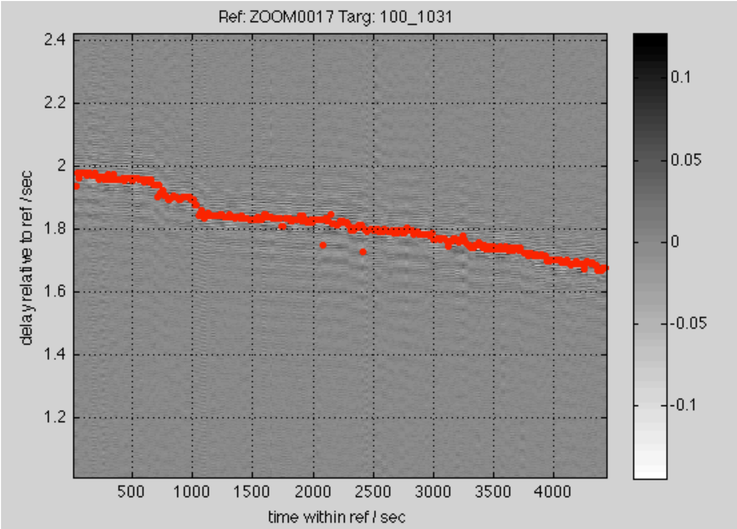
Cross-correlation



Correlation in action

- Close mic vs. video camera mic





- Short-time cross-correlation