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Lecture 3 : Questions and Solutions What is a Linear Time Invariant (LTI) System? *Signals and systems by R.K Kanodia book*
REVIEW

Signal Operations Example #1 Signals & Systems - Causal & Non-causal signals - working examples Lecture 1,
Introduction | MIT RES.6.007 Signals and Systems, Spring 2011 causal /non-causal ,linear /non-linear ,time variant /invariant
,static /dynamic , stable /unstable Linear, Time Invariant, and Causal Systems Lecture 2, Signals and Systems: Part 1 | MIT
RES.6.007 Signals and Systems, Spring 2011 EECS: Module 19 - Solutions to Linear Time Varying Systems SOLUTIONS
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Signals and Systems 2nd Edition Oppenheim Solutions Manual 1. Chapter 2 Answers 2.1. (a) We know that $y_i[n] = x[n] * h[n] = \sum_{k=-\infty}^{\infty} h[k]x[n-k]$ (S2.1-1) The signals $x[n]$ and $h[n]$ are as shown in Figure S2.1. From this figure, we can easily see that the above convolution sum reduces to $y_i[n] = \sum_{l=-l}^{n+l} h[l]x[n-l] = 2x[n+1] \dots$

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$x_2'' = Ay_1(t) + By_2(t)$ where $y_i(t)$, $i = 1;2$, are the corresponding outputs to $x_i(t)$, $i = 1;2$. ii.If $x(t) = u(t)$ then $y(t) = r(t)$ $r(t)$ 1) and if $x_1(t) = u(t)$ the corresponding output is $y_1(t) = y(t)$. System is time-invariant. In general, if $x_1(t) = x(t)$ the

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output is $1 - T Z^{-1} t T$. $x_1(z)$

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