



Question 2 ..... (14 points)

Let  $h[n]$  denote a real-valued impulse response of an LTI system, and let  $H(\omega)$ ,  $A(\omega)$ , and  $\phi(\omega)$  denote the corresponding frequency response, amplitude response, and phase response, respectively.

(a) [2 points] For what frequencies  $\omega$  is the frequency response  $H(\omega)$  real-valued for *any* real-valued  $h[n]$ ?

(b) [2 points] Under what conditions on  $h[n]$  (in addition to being real-valued) is the frequency response  $H(\omega)$  real-valued for *all* frequencies  $\omega$ .

(c) [2 points] If  $A(\pi/4) = 10$ , what is  $A(-\pi/4)$ ?

(d) [2 points] If  $A(\pi/4) = 10$ , what is  $A(9\pi/4)$ ?

(e) [2 points] If  $A(\pi/4) = 10$ , what is  $A_{dB}(\pi/4)$ ?

(f) [2 points] If  $\phi(\pi/4) = \pi/2$ , what is  $\phi(-\pi/4)$ ?

(g) [2 points] If  $\phi(\pi/4) = \pi/2$ , what is  $\phi(9\pi/4)$ ?



Question 4 ..... (12 points)

Let  $h[n] = (1/3)^n u[n] - 2(1/3)^{n-1} u[n-1]$  be the impulse response of an LTI system. Let  $x[n] = 2^n u[-n-1]$  denote the input to this system, and let  $y[n]$  denote the corresponding output.

(a) [2 points] What is the Z-transform  $H(z)$  of this system? (Include the ROC!)

(b) [2 points] Is the system stable? (Why or why not?)

(c) [2 points] Is the system causal? (Why or why not?)

(d) [2 points] What is the Z-transform  $X(z)$  of the input  $x[n]$ ? (ROC!)

(e) [2 points] What is the Z-transform  $Y(z)$  of the output  $y[n]$ ? (ROC!)

(f) [2 points] What is the system output  $y[n]$ ?