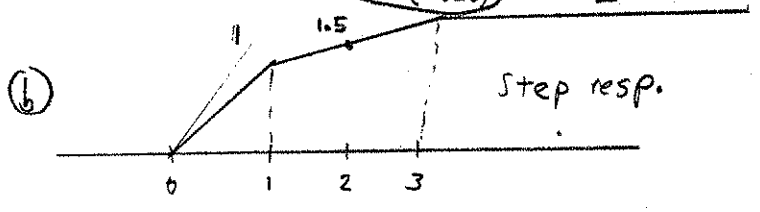
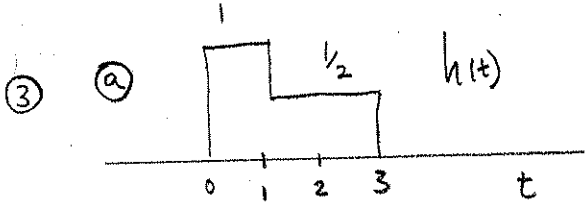
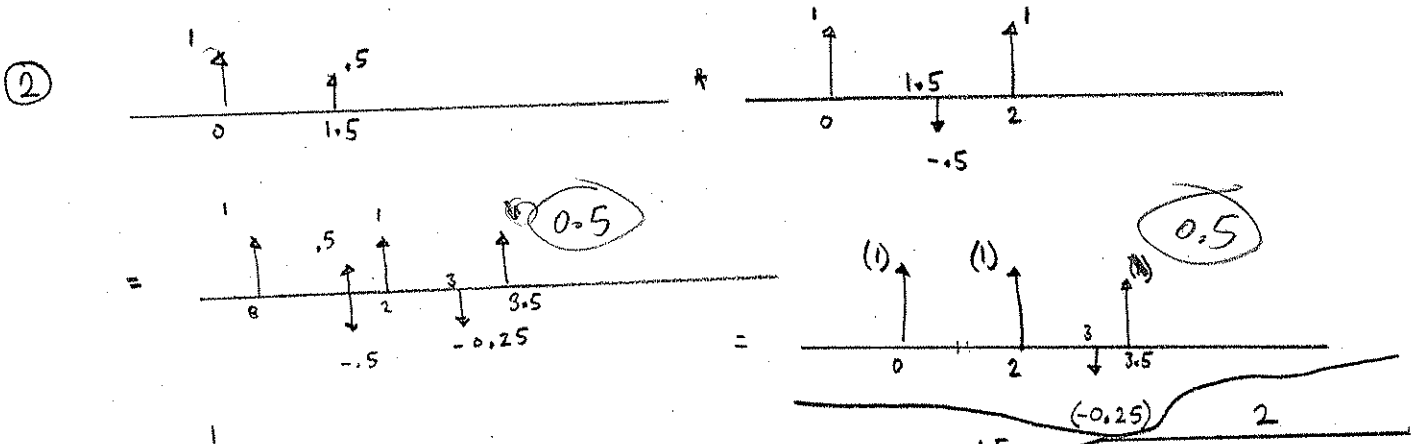
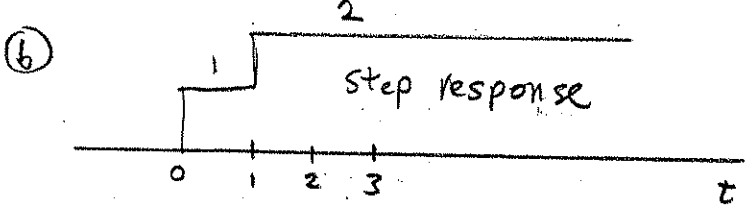
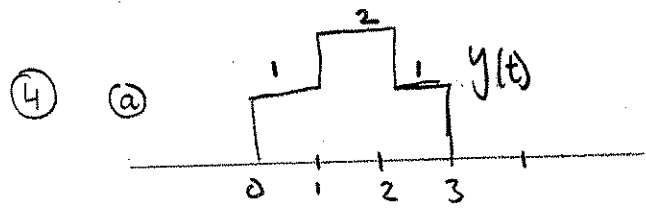


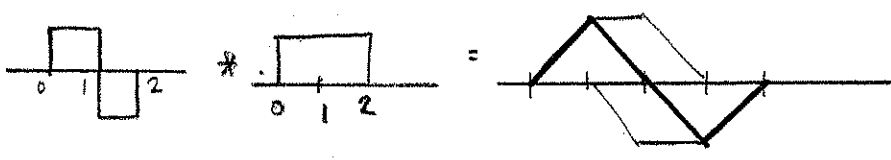
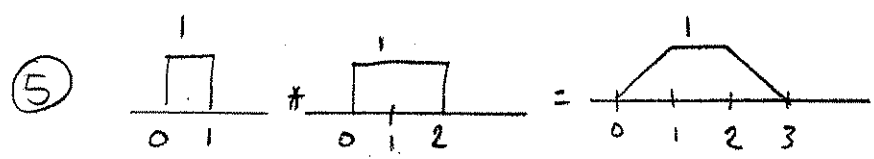
$s(t) = x(t) \cdot f(t)$

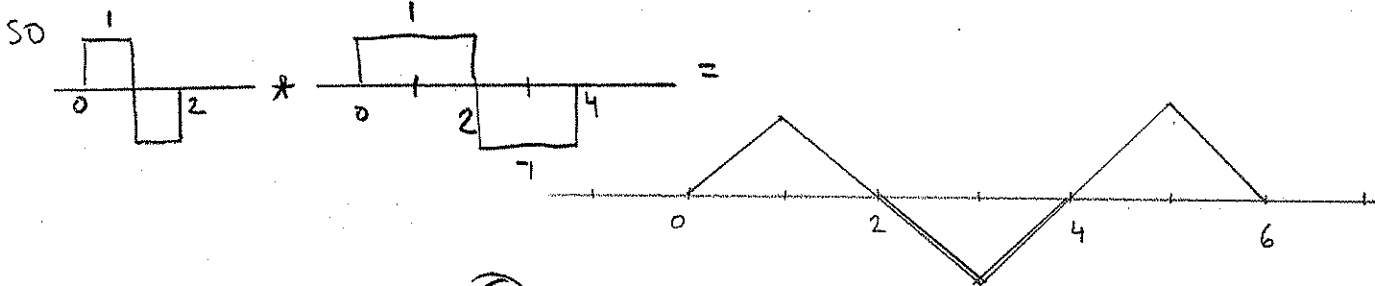


④ (c) dc gain = 2.

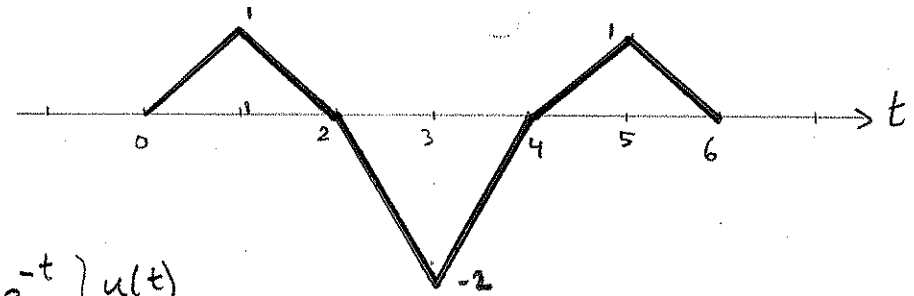


④ (c)  $h(t) = \frac{d}{dt}(\text{step resp.})$





(5)



(6)  $h(t) = \{3e^{-t} + 2e^{-2t} + e^{-t}\} u(t)$

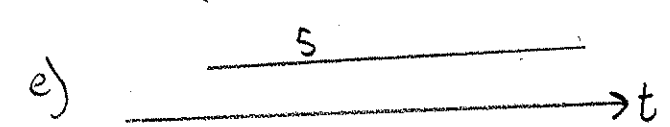
a)  $H(s) = \frac{3}{s+1} + \frac{2}{s+2} + \frac{1}{s+1} = \frac{4}{s+1} + \frac{2}{s+2} = \frac{4(s+2) + 2(s+1)}{(s+1)(s+2)}$

$H(s) = \frac{6s + 10}{s^2 + 3s + 2}$

b)  $y'' + 3y' + 2y = 6x' + 10x$

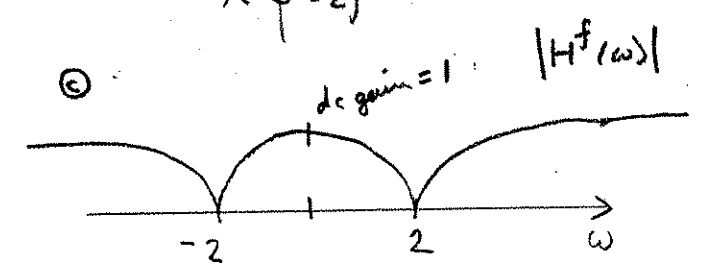
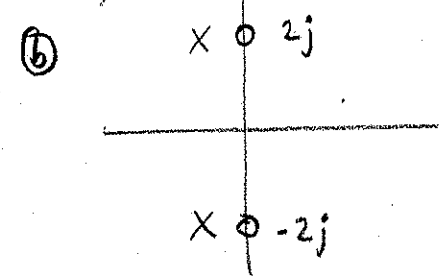
c) poles  $s = -1, s = -2$

d) dc gain =  $H(s=0) = 5$



f) steady state output = 5.

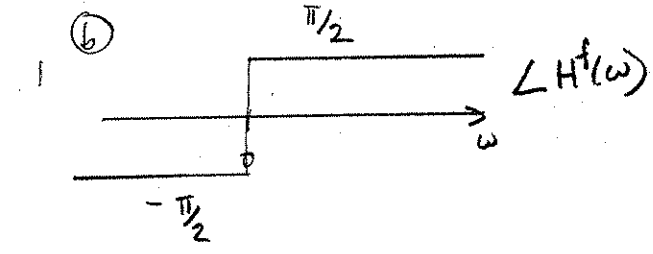
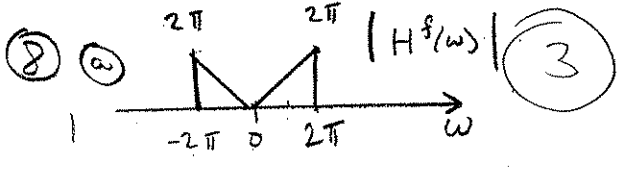
(7)  $\frac{K(s-2j)(s+2j)}{(s+1-2j)(s+1+2j)} = \frac{(s^2+4)K}{s^2+2s+5} = H(s)$



$H(s=0) = \frac{4}{5}K = 1 \rightarrow K = \frac{5}{4} = 1.25$

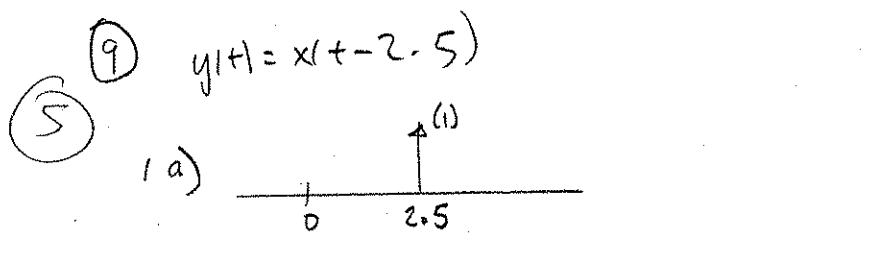
$y'' + 2y + 5y = 1.25x'' + 5x$

d)  $h(t) = Ae^{-t} \cos(2t + \theta) u(t)$

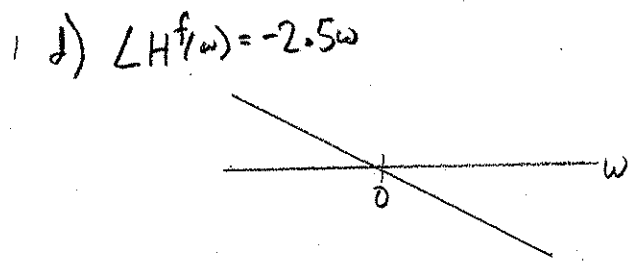
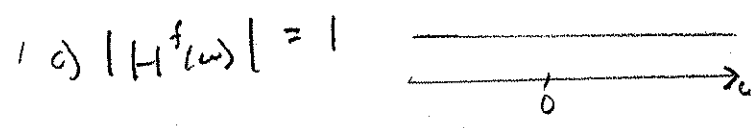


c) 
$$y(t) = 2\pi \cos(\pi t + \frac{\pi}{2})$$

$$= -2\pi \sin(\pi t)$$



b) 
$$H^f(w) = e^{-j2.5w}$$



4

10

h	v/2
1	6
2	2
3	1
4	7
5	8
6	5
7	3
8	4

3 11

sys	output
1	3
2	4
3	6
4	1
5	5
6	2

e) 
$$y(t) = 1 + 2 \cos(\pi(t-2.5)) + 4 \cos(3\pi(t-2.5))$$

#	points
1	2
2	2
3	3
4	3
5	4
6	6
7	5
8	3
9	5
10	4
11	3

~~40~~ 40