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continuous and discrete signals are defined as $E_{\infty} = \int_{-\infty}^{\infty} |x(t)|^2 dx$ and E

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$E_{\infty} = \lim_{T \rightarrow \infty} \frac{1}{2T} \int_{-T}^T |x(t)|^2 dx$ and $P_{\infty} = \lim_{N \rightarrow \infty} \frac{1}{2N+1} \sum_{n=-N}^N |x[n]|^2$. Using these we can compute each part of the given problem. Part (a): For this signal we find $E_{\infty} = \int_0^{\infty} e^{-4t} dt = \frac{1}{4}$, and $P_{\infty} = \lim_{T \rightarrow \infty} \frac{1}{2T} \int_0^{\infty} e^{-4t} dt = \frac{1}{4}$

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$y(t)$; then $cx(t)$ SYSTEM $cy(t)$ for any constant c .

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The second operator H^{-1} is the inverse of the first operator H . Hence, the input

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$x(t)$ is passed through the cascade connection of H and H^{-1} completely unchanged. Signals two situations equivalent, provided the H is time invariant.

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signals and systems 4. The continuous-

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time system consists of two integrators and two scalar multipliers. Write a differential equation that relates the output $y(t)$ and the input $x(t)$.

$$\frac{d^2 y(t)}{dt^2} + 2 \frac{dy(t)}{dt} + y(t) = x(t) \quad (1)$$

Since $w(t)$ is the input to the second integrator, we have

$$\frac{dy(t)}{dt} = w(t) \quad (2)$$

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