



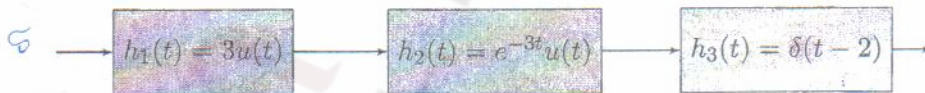
5x1=25

SERIAL No.

- SECTION: SECTION 1, SUN, TUE, THUS 09:00-10:00
 SECTION 2, SUN, TUE, THUS 11:00-12:00
 SECTION 3, MON, WED 09:30-11:00

| Write your answers here | | | | | | | | | | | | | |
|-------------------------|---|----|---|----|---|----|---|----|---|----|---|----|---|
| 1 | a | 2 | e | 3 | e | 4 | d | 5 | e | 6 | e | 7 | c |
| 8 | d | 9 | a | 10 | d | 11 | b | 12 | e | 13 | e | 14 | c |
| 15 | c | 16 | e | | | | | | | | | | |

1. The impulse response of the continuous-time cascade system shown is



- (a) $3e^{-6}\delta(t-2)$
 b. $u(t-2) - e^{-3(t-2)}u(t-2)$
 c. none of these
 d. $3u(t) + e^{-3t}u(t) + \delta(t-2)$
 e. $3e^{-3t}u(t)\delta(t-2)$

2. The LTI system with $h(t) = \delta(t-1) + e^t u(-t-1)$ is

- a. causal and nonstable
 b. causal and stable
 c. noncausal but stable
 d. need more information
 (e) noncausal and nonstable

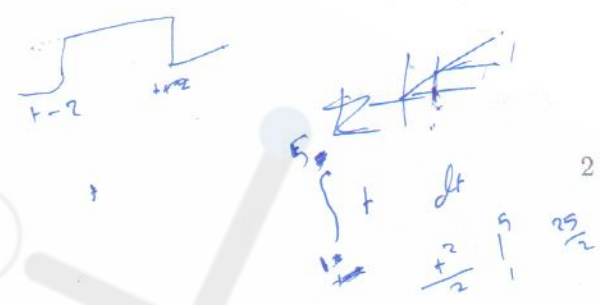
3. The output of a system is given by $y(t) = (ax(t) + 1)^2 - x(t)^2 - b$. For which values of a and b is the system linear.

- a. $a = \pm 1, b = 0$
 b. need more information

$a^2 x^2(t) + 2ax(t) + 1 - x^2(t) - b$

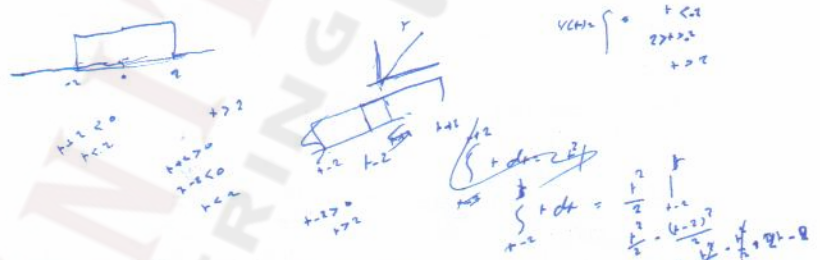
No. 3

- c. $a = -1, b = 1$
- d. $a = 1, b = 1$
- e. $a = \pm 1, b = 1$**



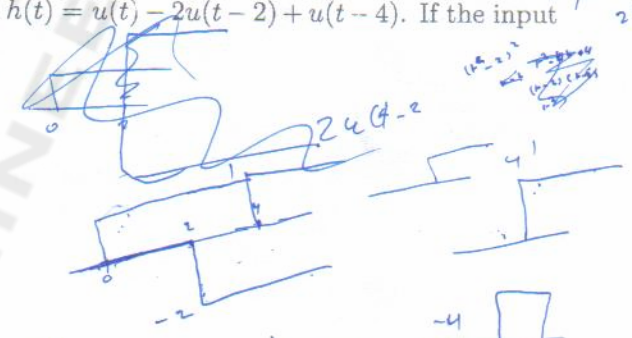
4. The input $x(t) = u(t+2) - u(t-2)$ is applied to an LTI system with impulse response $h(t) = t$. The value of the output signal at $t = 3$ is $y(3) =$

- a. zero
- b. 12
- c. 15/2
- d. 25/2**
- e. none of these



5. Consider a continuous-time LTI system with impulse response $h(t) = u(t) - 2u(t-2) + u(t-4)$. If the input signal $x(t) = u(t)$, then the response $y(t)$ at $t = 4$ is

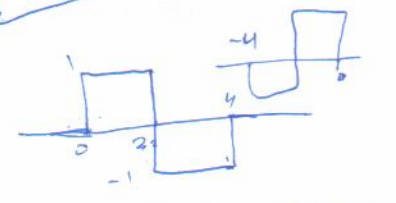
- a. 1
- b. -1
- c. 2
- d. none of these
- e. zero**



6. The integral $\int_{-\infty}^{\infty} (t+2)\delta(4-2t)dt$ has the value

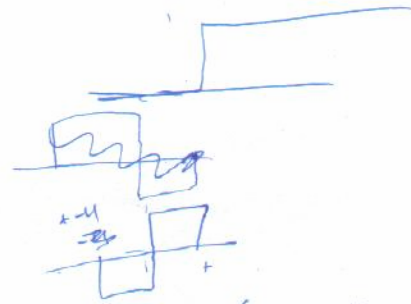
- a. 2
- b. 4
- c. 8
- d. none of these
- e. zero**

$\delta(4-2t) = \delta(2(2-t)) = \frac{1}{2} \delta(t-2)$



7. Which of the following statements is FALSE for convolution?

- a. $x(t) * [y(t)z(t)] = [x(t) * y(t)]z(t)$
- b. all are correct
- c. $x(t) * \delta(t-t_0) = x(t-t_0)$**
- d. $x(t) * y(t) = y(t) * x(t)$
- e. $x(t) * [y(t) + z(t)] = [x(t) * y(t)] + [x(t) * z(t)]$



8. Consider the following statements

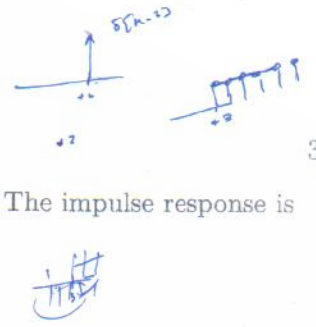
- S1: The set of the two functions $\{1/2, (t-1/2)\}$ is orthogonal over interval (0,1).
- S2: The set of the two functions $\{1, (2t-1)\}$ is orthonormal over interval (0,1).

- a. S1 is true but S2 is false
- b. S1 and S2 are false
- c. none of these
- d. S1 and S2 are true**
- e. S1 is false but S2 is true

$\int_0^1 \frac{1}{2} \cdot (t-1/2) dt = \frac{1}{2} \int_0^1 (t-1/2) dt = \frac{1}{2} [\frac{t^2}{2} - \frac{1}{2}t]_0^1 = \frac{1}{2} [\frac{1}{2} - \frac{1}{2}] = 0$
 $\int_0^1 1 \cdot (2t-1) dt = \int_0^1 (2t-1) dt = [t^2 - t]_0^1 = 1 - 1 = 0$

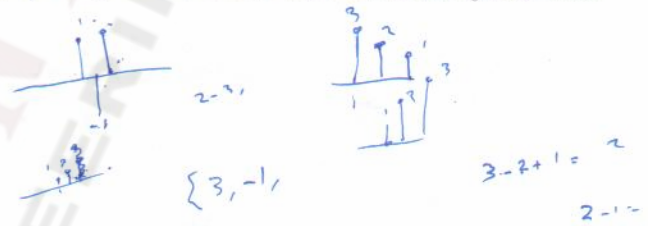
9. An LTI system has input $x[n] = \delta[n - 2]$ which gives the output $y[n] = u[n - 3]$. The impulse response is

- a. $h[n] = u[n - 1]$ ✓
- b. $h[n] = u[n - 3] - u[n - 2]$
- c. $h[n] = u[n - 3] - u[n - 1]$
- d. $h[n] = u[n - 2]$
- e. $h[n] = u[n]$



10. Calculate the output $y[n]$ when the sequence $x[n] = \{1, -1, 1\}$ is input to a linear time-invariant system that has an impulse response given by $h[n] = \{3, 2, 1\}$.

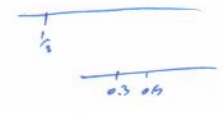
- a. none of these
- b. $y[n] = \{3, -2, 1\}$
- c. $y[n] = \{3, 8, 14, 8, 3\}$
- d. $y[n] = \{3, -1, 2, 1, 1\}$ ✓
- e. $y[n] = \{-1, 8, 5, 8, 3\}$



11. Given the function $x(t) = \text{Sa}\left(\frac{t - \pi}{3}\right)$. The second null will occur at $t =$

- a. 6π
- b. 4π ✓
- c. 7π
- d. 3π
- e. none of these

$\frac{\text{sinc}(n\pi)}{n\pi}$



12. Calculate the energy in the signal $x(t) = 5t$, for $0 \leq t < 1$ and $x(t) = 0$ otherwise.

- a. 25
- b. infinity
- c. none of these
- d. $25/4$
- e. $25/3$ ✓

$25 \int_0^1 t^2 dt = \frac{25}{3} t^3 \Big|_0^1 = \frac{25}{3}$

13. The continuous-time signal $x(t) = 4 \sin(4\pi t) - 6 \cos(6\pi t)$

- a. is periodic with fundamental period $T_0 = 2$
- b. is periodic with fundamental period $T_0 = 1$
- c. is periodic with fundamental period $T_0 = 1/2$
- d. is not periodic
- e. none of these ✓

$\omega_0 = \frac{2\pi}{T_1}$
 $\frac{2\pi}{4T} = \frac{1}{2} \Rightarrow T = 4$
 $\omega_2 = \frac{2\pi}{T_2} = \frac{2\pi}{6T} = \frac{1}{3}$
 $\frac{1/2}{1/3} = \frac{3}{2} = \frac{6}{4}$
 $u(-6-k)$

14. Evaluate the following integral, $\int_{-\infty}^{\infty} u(\tau - 1)u(t - \tau)d\tau$.

- a. $tu(t)$
- b. $(t - 1)u(t - 1)$
- c. $t - 1$ ✓
- d. $(t - 1)u(t)$

$4\pi = \omega$
 $\frac{2\pi}{T_0} = 4\pi \Rightarrow T_0 = \frac{1}{2}$
 $\frac{1}{2} \sim \frac{1}{2}$
 $T_0 = \frac{2\pi}{6\pi} = \frac{1}{3}$
 $\frac{1/2}{1/3} = \frac{3}{2} = \frac{6}{4}$

No. 3

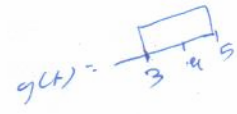
e. $tu(t-1)$

15. If $x(t) = u(t+1)u(1-t) - 2r(t-3)$, then the generalized derivative of $x(t)$ is

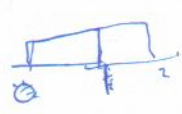
- a. none of these
- b. $\delta(t+1)\delta(1-t) - 2$
- c. $\delta(t+1)\delta(1-t) - 2u(t-3)$
- d. $\delta(t+1) - \delta(t-1) - 2u(t-3)$
- e. $\delta(t)u(1-t) + u(t+1)\delta(-t) - 2$

16. Given $f(t) = \text{rect}\left(\frac{2t-1}{2}\right)$ and $g(t) = \text{rect}\left(\frac{t-4}{2}\right)$. $g(t)$ can be expressed as

- a. $g(t) = f(t/2 - 3/2)$
- b. none of these
- c. $g(t) = f(2t-3)$
- d. $g(t) = f(2t-3/2)$
- e. $g(t) = f(t/2-3)$

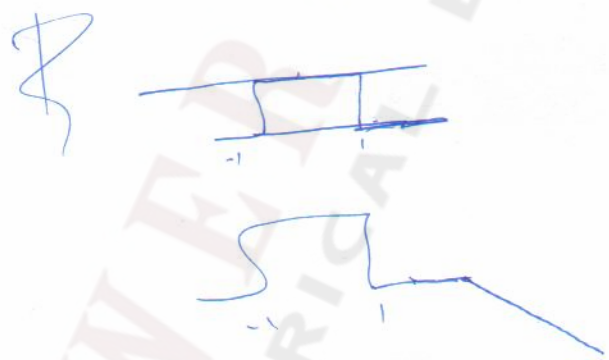


$f(t) = 2\left(t - \frac{1}{2}\right)$



$f\left(\frac{t}{2} + 3\right)$

$u(1-t)$
 $u(-(t-1))$



$-2u(t-3)$

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