



Advanced Topics in System and Signal Theory: A Mathematical Approach (Foundations in Signal Processing, Communications and Networking)

Volker Pohl, Holger Boche

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The requirement of causality in system theory is inevitably accompanied by the appearance of certain mathematical operations, namely the Riesz projection, the Hilbert transform, and the spectral factorization mapping. A classical example illustrating this is the determination of the so-called Wiener filter (the linear, minimum means square error estimation filter for stationary stochastic sequences [88]). If the filter is not required to be causal, the transfer function of the Wiener filter is simply given by $H(\omega) = \frac{S_{xy}(\omega)}{S_{xx}(\omega)}$, where $S_{xy}(\omega)$ and $S_{xx}(\omega)$ are certain given functions. However, if one requires that the estimation filter is causal, the transfer function of the optimal filter is given by $H(\omega) = P^{-1} S_{xy}(\omega)$, where P is the so-called Riesz projection. Thus, compared to the non-causal filter, two additional operations are necessary for the determination of the causal filter, namely the spectral factorization mapping $S_{xx}(\omega) = |G(\omega)|^2$, and the Riesz projection P .

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