

Basic theorems:  $x = \begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{bmatrix}$

$$x^T A x$$

$A$  is  $n \times n$  symmetric matrix:

$$\nabla(x^T A x) = 2 A x$$

$$x^T a$$

$a$  is  $n \times 1$  column vector

$$\nabla(x^T a) = a$$

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Bilinear

$$ax^2 + by^2 + cz^2 + dxy + eyz + fzx$$

$$\begin{bmatrix} x & y & z \end{bmatrix} \begin{bmatrix} A & B & C \\ D & E & F \\ G & H & I \end{bmatrix} \begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} x & y & z \end{bmatrix} \begin{bmatrix} a & \frac{d}{2} & \frac{f}{2} \\ \frac{d}{2} & b & \frac{e}{2} \\ \frac{f}{2} & \frac{e}{2} & c \end{bmatrix} \begin{bmatrix} x \\ y \\ z \end{bmatrix}$$

$$\begin{bmatrix} x & y & z \end{bmatrix} \begin{bmatrix} Ax + By + Cz \\ Dx + Ey + Fz \\ Gx + Hy + Iz \end{bmatrix}$$

$$= Ax^2 + Bxy + Cxz + Dyx + Ey^2 + Fyz + Gxz + Hzy + Iz^2$$

$$(B + D \equiv d; \quad B=0, D=d \quad \text{or} \\ B = \frac{1}{3}d, D = \frac{2}{3}d \quad \text{or}$$

$$\text{Best} \quad \longrightarrow \quad B = \frac{1}{2}d = D .)$$

Note that matrix element in  $i^{\text{th}}$  row,  $j^{\text{th}}$  column ends up multiplying  $x_i$  and  $x_j$

$$[x_1, x_2, x_3] \begin{bmatrix} A_{11} & A_{12} & A_{13} \\ A_{21} & A_{22} & A_{23} \\ A_{31} & A_{32} & A_{33} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix}$$

$A_{21} = A_{12}$   
 $A_{31} = A_{13}$   
 $A_{32} = A_{23}$

$$= A_{11} x_1^2 + A_{22} x_2^2 + A_{33} x_3^2$$

$$+ 2A_{12} x_1 x_2 + 2A_{23} x_2 x_3 + 2A_{13} x_1 x_3$$

From the red box on page 2 we see

$$\begin{bmatrix} x_1 & x_2 & \dots & x_n \end{bmatrix} \begin{bmatrix} A_{11} & & & \\ & \dots & & \\ & & A_{ij} & \\ & & & \dots \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{bmatrix}$$

equals

$$\sum_{i=1}^n \sum_{j=1}^n A_{ij} x_i x_j$$

## Summary

$$ax_1^2 + bx_1x_2 + cx_2^2 + dx_1x_3 + ex_3^2 + \dots$$

$$\begin{matrix} & & ||| \\ [x_1 \ x_2 \ \dots \ x_n] & \left[ \begin{array}{c} \text{symmetric} \\ \text{matrix} \\ A_{ij} \end{array} \right] & \left[ \begin{array}{c} x_1 \\ \vdots \\ x_n \end{array} \right] \end{matrix}$$

$$\sum_{i=1}^n \sum_{j=1}^n A_{ij} x_i x_j .$$

Rule  $ax + by + cz$  linear form

$$= \begin{bmatrix} x & y & z \end{bmatrix} \begin{bmatrix} a \\ b \\ c \end{bmatrix} \text{ or } [a \ b \ c] \begin{bmatrix} x \\ y \\ z \end{bmatrix}$$

$\leftarrow x^T a = a^T x \rightarrow$

$$= \sum_{i=1}^n a_i x_i$$


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$$\frac{\partial \text{linear form}}{\partial x_2} = b \equiv a_2$$

$$\frac{\partial \text{---}}{\partial x_1} = a_1$$

$$\frac{\partial \text{---}}{\partial x_3} = a_3$$

$$\begin{bmatrix} \frac{\partial}{\partial x_1} \\ \frac{\partial}{\partial x_2} \\ \frac{\partial}{\partial x_3} \\ \vdots \\ \frac{\partial}{\partial x_n} \end{bmatrix} (a^T x) = \begin{bmatrix} a_1 \\ a_2 \\ a_3 \\ \vdots \\ a_n \end{bmatrix} = a$$

$$\uparrow \text{gradient} \equiv \nabla$$

Bilinear

$$ax^2 + by^2 + cz^2 + dxy + eyz + fzx$$

$$\begin{bmatrix} x & y & z \end{bmatrix} \begin{bmatrix} A & B & C \\ D & E & F \\ G & H & I \end{bmatrix} \begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} x & y & z \end{bmatrix} \begin{bmatrix} a & \frac{d}{2} & \frac{f}{2} \\ \frac{d}{2} & b & \frac{e}{2} \\ \frac{f}{2} & \frac{e}{2} & c \end{bmatrix} \begin{bmatrix} x \\ y \\ z \end{bmatrix}$$

$$\begin{bmatrix} x & y & z \end{bmatrix} \begin{bmatrix} Ax + By + Cz \\ Dx + Ey + Fz \\ Gx + Hy + Iz \end{bmatrix}$$

$$= Ax^2 + Bxy + Cxz + Dyx + Eyz + Fyz + Gxz + Hxy + Iz^2$$

$$(B+D \equiv d; B=0, D=d \text{ or } B=\frac{1}{2}d, D=\frac{1}{2}d \text{ or } B \neq \frac{1}{2}d \rightarrow B = \frac{1}{2}d = D)$$

Note that matrix element in  $i^{\text{th}}$  row,  $j^{\text{th}}$  column equals up multiplying  $x_i$  and  $x_j$

Take  $\frac{\partial}{\partial x_2} = \frac{\partial}{\partial y}$  (bilinear form) :

$$\frac{\partial}{\partial y} (\text{quad form}) = 2by + dx + ez$$

$$\equiv 2A_{22}x_2 + 2A_{21}x_1 + 2A_{23}x_3$$

$$= 2 \begin{bmatrix} A_{21} & A_{22} & A_{23} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix}$$

$$\frac{\partial}{\partial x} = 2 \begin{bmatrix} A_{11} & A_{12} & A_{13} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix}$$

$$\frac{\partial}{\partial z} = 2 \begin{bmatrix} A_{31} & A_{32} & A_{33} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix}$$

$$\nabla(x^T Ax) = \begin{bmatrix} \frac{\partial}{\partial x} \\ \frac{\partial}{\partial y} \\ \frac{\partial}{\partial z} \end{bmatrix} x^T Ax = 2 \begin{bmatrix} A_{11} & A_{12} & A_{13} \\ A_{21} & A_{22} & A_{23} \\ A_{31} & A_{32} & A_{33} \end{bmatrix} \begin{bmatrix} x \\ y \\ z \end{bmatrix}$$

So:

$$\nabla x^T A x = 2 A x$$

$$\nabla x^T a = \nabla a^T x = a$$

(A symmetric)



Wiener Filter in general.

Measure  $x(n)$  = stationary  
Wish to estimate  $d(n)$  =

Assume: Know  ~~$x$~~   $r_x(n)$  &  $r_d(n)$ .

Estimator:  $\hat{d}(n) = \sum_{k=k_1}^{k_2} x(n-k) w(k)$

application  $\hat{d}(n) = x(n) w(0)$  denoiser

$\hat{d}(n) = x(n) w(0) + x(n-1) w(1) + x(n-2) w(2)$

$\hat{d}(n) = x(n) w(0) + x(n-1) w(1)$  3-term denoiser

$x(n+1) w(-1)$  smoother

~~$\hat{d}(n) = x(n+1)$~~

$d(n) = x(n+1)$ ,  $\hat{d}(n) = x(n) w(0) + x(n-1) w(1) + x(n-2) w(2)$

predictor

In general

$$\hat{d}(n) = \sum_k x(n-k) w(k)$$

$$= [x(n) \ x(n-1) \ \dots] \begin{bmatrix} w(0) \\ w(1) \\ \vdots \\ w(\dots) \end{bmatrix}$$

$$= x^T w$$

error  $\hat{d}(n) - d(n) = x^T w - d$

Squared error  $= [x^T w - d] [x^T w - d]$

$$\begin{aligned}
 (\text{err})^2 &= [x^T w - d][x^T w - d] \\
 &= [w^T x - d][x^T w - d] \\
 &= w^T x x^T w - d x^T w - w^T x d + d^2
 \end{aligned}$$

$$\mathcal{E}\{e^2\} = w^T \mathcal{E}\{x x^T\} w - 2 \mathcal{E}\{d x^T\} w + d^2$$

$$x x^T = \begin{bmatrix} x(n) \\ x(n-1) \\ x(n-2) \\ \vdots \end{bmatrix} [x(n) \dots x(n-2)]$$

$$= \begin{bmatrix} x(n)^2 & x(n)x(n-1) & x(n)x(n-2) & \dots & x(n)x(n-k) \\ x(n-1)x(n) & x(n-1)x(n-1) & x(n-1)x(n-2) & \dots & \dots \\ \dots & \dots & \dots & \dots & \dots \\ \dots & \dots & \dots & \dots & \dots \\ \dots & \dots & \dots & \dots & \dots \end{bmatrix}$$

$$\mathcal{E}\{x x^T\} = \begin{bmatrix} r_x(0) & r_x(1) & \dots \\ r_x(1) & \dots & \dots \\ \dots & \dots & \dots \end{bmatrix} \quad \text{symmetric matrix} \\
 \text{autocorrelation}$$

$$dx^T = d(n) [x(n) \quad x(n-1) \quad \dots \quad x(n-k)]$$

$$E [dx^T] = \begin{bmatrix} r_{dx}(0) & r_{dx}(1) & \dots & r_{dx}(n) \end{bmatrix}$$

vectors of cross-correlations.

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$$E\{e^2\} = w^T E\{xx^T\}w - 2 E\{dx^T\}w + d^2$$

$$\nabla_w E\{e^2\} = 0 = 2 \underset{r_d}{E\{xx^T\}}w - 2 \underset{r_{dx}}{E\{dx^T\}} = 0$$

↑  
to minimize

Wiener-Hopf f

$$r_d w = r_{dx}$$

$$w = r_d^{-1} r_{dx}$$