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noise theory is phrased in terms familiar to the electrical or electronics engineer, in which he states his problems and presents the solutions 10). Voltage and current, impedance and admittance are the concepts, frequency analysis and Fourier transforms are the methods used to attack noise problems. Also new

~~On the theory of linear noisy systems—Pure~~

A later version of the theory by Norbert Wiener added a 7th concept ('feedback') which changed the model from a linear to cyclical model. ... One of the key goals for people who use this theory is to identify the causes of noise and try to minimize them to improve the quality of the message.

~~Shannon Weaver Model of Communication | 7 Key Concepts (2020)~~

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Dear colleagues! The idea to publish Scientific Journal devoted to theory and practice of controlling noise and vibration under the aegis of the famous Baltic State Technical University 'VOENMECH' named after D.F. Ustinov was stated by the participants of the Fifth All-Russian research and practical conference with international participation 'Excessive noise and vibration protection ...

~~Home page — Noise Theory and Practice~~

In statistics and control theory, Kalman filtering, also known as linear quadratic estimation (LQE), is an algorithm that uses a series of measurements observed over time, containing statistical noise and other inaccuracies, and produces estimates of unknown variables that tend to be more accurate than those based on a single measurement alone, by estimating a joint probability distribution over the variables for each timeframe.

~~Kalman filter — Wikipedia~~

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In the microwave tube case, however, the findings were based heavily upon the physical nature of the electron beam, and it was not immediately clear that a general theory of noise performance for any linear amplifier could be made without referring again to

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some detailed physical mechanism.

~~Circuit Theory of Linear Noisy Networks (The MIT Press ...~~

LINEAR MODELS Polynomial Curve Fitting Example. Continuous signal $x(t)$ is modeled as a polynomial of degree $p-1$ in additive noise: $x(t) = \theta_1 + \theta_2 t + \dots + \theta_{p-1} t^{p-1} + w(t)$. Suppose that we are given $\{x(t_n)\}_{n=0}^{N-1}$. Define $x = [x(t_0), \dots, x(t_{N-1})]^T$, $w = [w(t_0), \dots, w(t_{N-1})]^T$, $\theta = [\theta_1, \dots, \theta_p]^T$, $H = \begin{bmatrix} 1 & t_0 & \dots & t_0^{p-1} \\ \vdots & \vdots & \dots & \vdots \\ 1 & t_{N-1} & \dots & t_{N-1}^{p-1} \end{bmatrix}$.

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a linear dynamic system excited by independent or uncorrelated random signals ("white noise"). This is a standard trick in the engineering applications of the Wiener theory [2-7]. The approach taken here differs from the conventional one only in the way in which linear dynamic systems are described. We shall

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~~A New Approach to Linear Filtering and Prediction Problems~~

A linear noise-removal filter will usually blur those features; a non-linear filter may give more satisfactory results (even if the blurry image may be more "correct" in the information-theoretic sense). Many nonlinear noise-removal filters operate in the time domain.

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