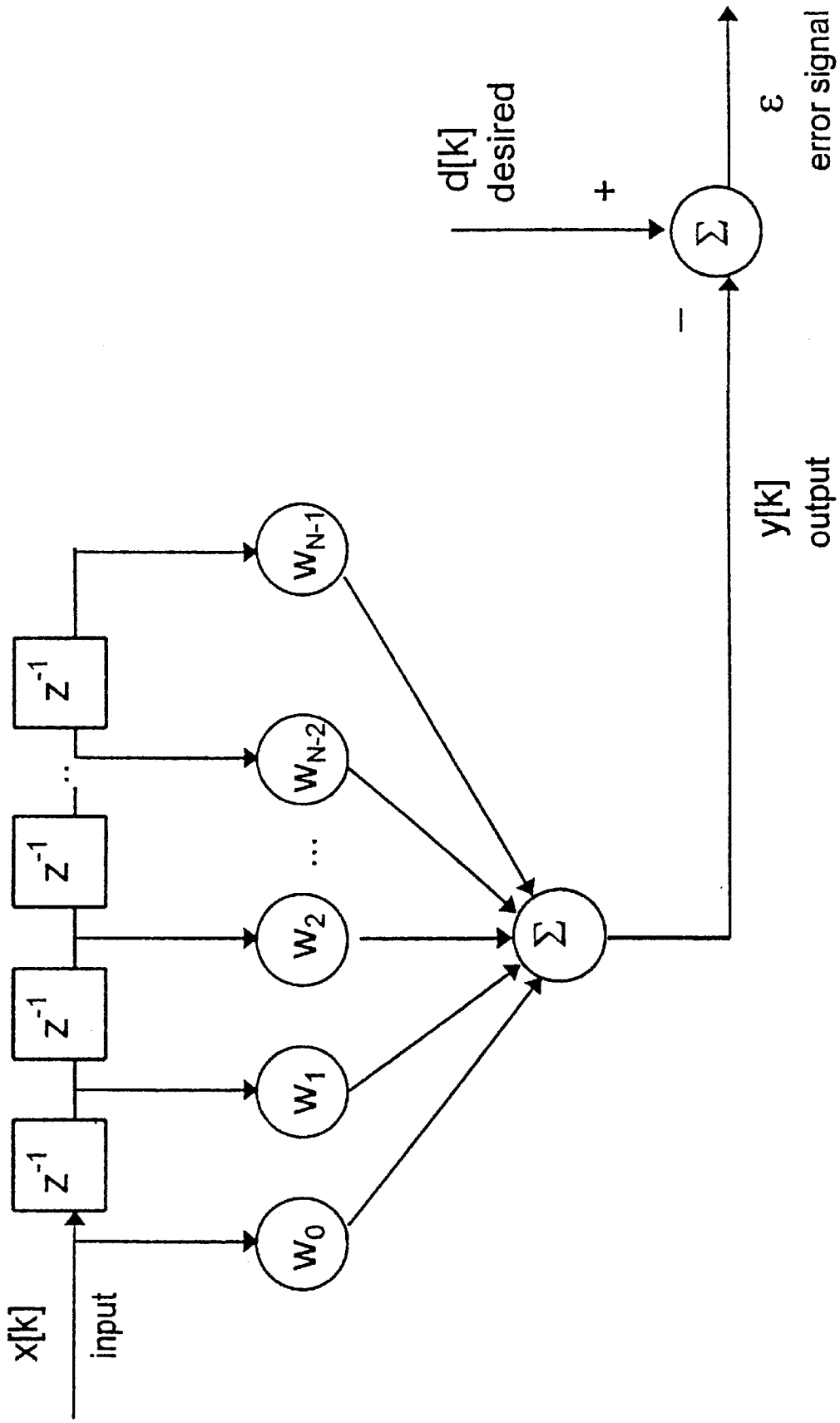
x[k]
input
$z^{-1}$
$z^{-1}$
$z^{-1}$
$z^{-1}$
$w_0$
$w_1$
$w_2$
$w_{N-2}$
$w_{N-1}$
Σ
y[k]
output
d[k]
desired
+
−
Σ
ε
error signal

FIG. 3