

**PPT
ON
RADAR SYSTEMS**

IV B.Tech II semester (JNTUH-R15)

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1

Unit I

BASICS OF RADAR



CONTENTS :: UNIT-I



- Radar History
- Nature Of Radar
- Maximum Unambiguous Range
- Radar Wave Forms
- Radar Range Equation
- Radar Block Diagram
- Radar Frequencies
- Radar Applications
- Related Problems

3

Radar History



- Radio Detection And Ranging
- Hertz
- Christian Hulsmeyer
- Albert H.Taylor and Leo C.Young
- Monostatic,Bistatic and Multistatic Radars

4

Nature of radar



- Radar operates by radiating energy
- Duplexer
- Echo signal
- Doppler effect

$$R = \frac{c T_R}{2}$$

- 1 Nautical mile=1.852 km

$$R(\text{km}) = 0.15 T_R(\mu\text{s}) \quad \text{or} \quad R(\text{nmi}) = 0.081 T_R(\mu\text{s})$$

5

Maximum Unambiguous Range



- Echoes that arrive after the transmission of the next pulse are called second-time-around(or multiple-time-around) echoes.
- The range beyond which targets appear as second-time-around echoes is called the

$$\text{Maximum } R_{\text{unamb}} = \frac{c}{2f_p} \text{ us range}$$

6

Radar Wave Forms



- Transmitted Power:: 1 Mega watt
- Pulse Width :: 1 Micro second
- Pulse Repetition Period :: 1 Milli second
- Average Power can be calculated as
Transmitted Power * Pulse Width * Pulse Repetition Frequency
- Energy :: Transmitted Power * Pulse Width

7

Radar Range Equation



- If the power of the radar transmitter is denoted by P_t , and if an isotropic antenna is used (one which radiates uniformly in all directions), the power density(watts per unit area) at a distance R from the radar is equal to the transmitter power divided by the surface area $4\pi R^2$ of an imaginary sphere of radius R .
Power density from isotropic antenna = $\frac{P_t}{4\pi R^2}$
- The power density at the target from an antenna with a transmitting gain G is
Power density from directive antenna = $\frac{P_t G}{4\pi R^2}$
- The measure of the amount of incident power intercepted by the target and reradiated back in the direction of the radar is denoted as the radar cross section σ , and is defined by the relation

$$\text{Power density of echo signal at radar} = \frac{P_t G \sigma}{4\pi R^2 4\pi R^2}$$

8

Radar Range Equation



- If the effective area of the receiving antenna is denoted A_e , the power P_r received by the radar is

$$P_r = \frac{P_t G}{4\pi R^2} \frac{\sigma}{4\pi R^2} A_e = \frac{P_t G A_e \sigma}{(4\pi)^2 R^4}$$

- The maximum radar range R_{max} is the distance beyond which the target cannot be detected. It occurs when the received echo signal power P_r just equals the minimum detectable signal S_{min} ,

$$R_{max} = \left[\frac{P_t G A_e \sigma}{(4\pi)^2 S_{min}} \right]^{1/4}$$

- Antenna theory gives the relationship between the transmitting gain and the receiving effective area of an antenna as

$$G = \frac{4\pi A_e}{\lambda^2}$$

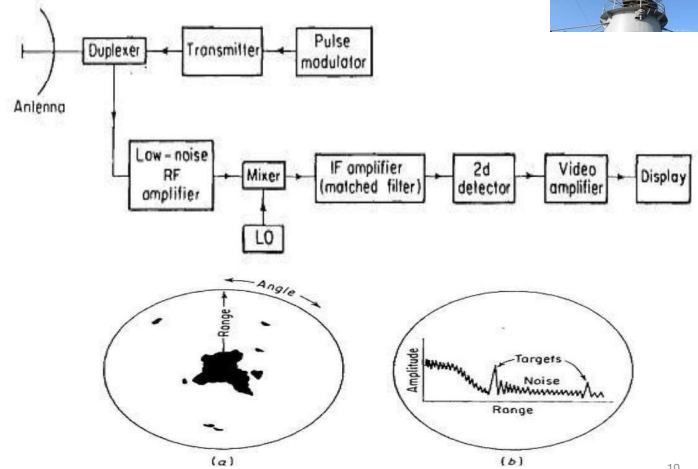
- Two other forms of the radar

$$R_{max} = \left[\frac{P_t G^2 \lambda^2 \sigma}{(4\pi)^3 S_{min}} \right]^{1/4}$$

$$R_{max} = \left[\frac{P_t A_e^2 \sigma}{4\pi \lambda^2 S_{min}} \right]^{1/4}$$

9

Radar Block Diagram



10

Radar Frequencies



| Band designation | Nominal frequency range | Specific radiolocation (radar) bands based on ITU assignments for region 2 |
|------------------|-------------------------|--|
| HF | 3–30 MHz | |
| VHF | 30–300 MHz | 138–144 MHz 216–225 |
| UHF | 300–1000 MHz | 420–450 MHz 890–942 |
| L | 1000–2000 MHz | 1215–1400 MHz |
| S | 2000–4000 MHz | 2300–2500 MHz 2700–3700 |
| C | 4000–8000 MHz | 5250–5925 MHz |
| X | 8000–12,000 MHz | 8500–10,680 MHz |
| K _u | 12.0–18 GHz | 13.4–14.0 GHz 15.7–17.7 |
| K | 18–27 GHz | 24.05–24.25 GHz |
| K _a | 27–40 GHz | 33.4–36.0 GHz |
| mm | 40–300 GHz | |

11

Radar Applications



- Air Traffic Control (ATC)
- Aircraft Navigation
- Ship Safety
- Remote Sensing
- Space
- Law Enforcement
- Military

12

RADAR EQUATIONS



- Prediction of Range Performance
- Minimum Detectable Signal
- Receiver Noise and SNR
- Integration of Radar pulses
- Radar Cross Section of targets
- Transmitted Power
- Pulse Repetition Frequencies
- System Losses

13

Prediction of Range Performance



- The simple form of the radar equation expressed the maximum radar range R_{\max} , in terms of radar and target parameters

$$R_{\max} = \left[\frac{P_t G A_e \sigma}{(4\pi)^2 S_{\min}} \right]^{1/4}$$

where P_t = transmitted power, watts
 G = antenna gain
 A_e = antenna effective aperture, m^2
 σ = radar cross section, m^2
 S_{\min} = minimum detectable signal, watts

- All the parameters are to some extent under the control of the radar designer, except for the target cross section σ .

14

Minimum Detectable Signal



- The weakest signal the receiver can detect is called the minimum detectable signal.
- A matched filter for a radar transmitting a rectangular-shaped pulse is usually characterized by a bandwidth B approximately the reciprocal of the pulse width τ ,

or $B\tau \approx 1$

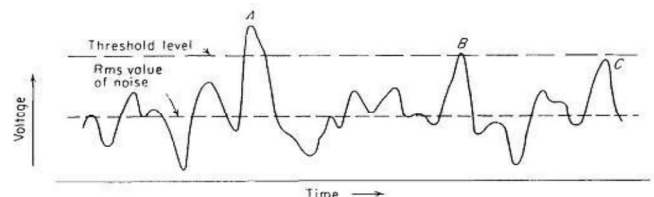
- Detection is based on establishing a threshold level at the output of the receiver.
- If the receiver output exceeds the threshold, a signal is assumed to be present. This is called threshold detection.

15

Minimum Detectable Signal



- Probability of Miss.
- Probability of False Alarm.



16

Receiver Noise and SNR

Available thermal-noise power = kTB_n



- Since noise is the chief factor limiting receiver sensitivity, it is necessary to obtain some means of describing it quantitatively
- Noise is unwanted electromagnetic energy which interferes with the ability of the receiver to detect the wanted signal.
- The available thermal-noise power generated by a receiver of bandwidth B_n (in hertz) at a temperature T (degrees Kelvin) is

17

Receiver Noise and SNR



- where k = Boltzmann's constant = 1.38×10^{-23} J/deg.
- Bandwidth and is given by

$$B_n = \frac{\int_{-\infty}^{\infty} |H(f)|^2 df}{|H(f_0)|^2}$$

$$F_n = \frac{N_o}{kT_0 B_n G_a} = \frac{\text{noise out of practical receiver}}{\text{noise out of ideal receiver at std temp } T_0}$$

$$F_n = \frac{S_i/N_i}{S_o/N_o}$$

- If the minimum detectable signal S_{min} , is that value of S_i corresponding to the minimum ratio of output (IF) signal-to-noise ratio $(S_o/N_o)_{min}$ necessary for detection.

18

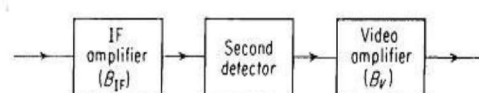
Receiver Noise and SNR



$$S_{min} = kT_0 B_n F_n \left(\frac{S_o}{N_o} \right)_{min}$$

$$R_{max}^4 = \frac{P_i G A_e \sigma}{(4\pi)^2 k T_0 B_n F_n (S_o/N_o)_{min}}$$

19



- The noise entering the IF filter (the terms filter and amplifier are used interchangeably) ability-density function $p(v) = \frac{1}{\sqrt{2\pi}\psi_0} \exp \left(-\frac{v^2}{2\psi_0} \right)$

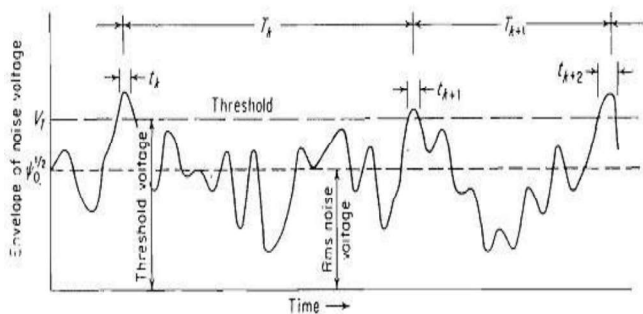
- The probability that the envelope of the noise voltage will lie between V_1 and V_2 is

$$\text{Probability } (V_1 < R < V_2) = \int_{V_1}^{V_2} \frac{R}{\psi_0} \exp \left(-\frac{R^2}{2\psi_0} \right) dR$$

- The probability that the noise voltage envelope will exceed the voltage threshold V_T is

$$\begin{aligned} \text{Probability } (V_T < R < \infty) &= \int_{V_T}^{\infty} \frac{R}{\psi_0} \exp \left(-\frac{R^2}{2\psi_0} \right) dR \\ &= \exp \left(-\frac{V_T^2}{2\psi_0} \right) = P_{ts} \end{aligned}$$

20



- The average time interval between crossings of the threshold by noise alone is denoted by $T_{fa} = \lim_{N \rightarrow \infty} \frac{1}{N} \sum_{k=1}^N T_k$ or T_{fa} .

21



$$P_{fa} = \frac{\sum_{k=1}^N t_k}{\sum_{k=1}^N T_k} = \frac{\langle t_k \rangle_{av}}{\langle T_k \rangle_{av}} = \frac{1}{T_{fa} B}$$

- Consider sine-wave signals of amplitude A to be present along with noise at the input to the IF filter. The frequency of the signal is the same as the IF midband frequency f_{IF} . The output of the envelope detector has a probability-density

$$p_s(R) = \frac{R}{\psi_0} \exp\left(-\frac{R^2 + A^2}{2\psi_0}\right) I_0\left(\frac{RA}{\psi_0}\right)$$

- where $I_0(Z)$ is the modified Bessel function of zero order and argument Z

22

Integration of Radar pulse



$$n_B = \frac{\theta_B f_p}{\theta_s} = \frac{\theta_B f_p}{6\omega_m}$$

where θ_B = antenna beamwidth, deg
 f_p = pulse repetition frequency, Hz
 θ_s = antenna scanning rate, deg/s
 ω_m = antenna scan rate, rpm

$$E_i(n) = \frac{(S/N)_1}{n(S/N)_n}$$

where n = number of pulses integrated

$(S/N)_1$ = value of signal-to-noise ratio of a single pulse required to produce given probability of detection (for $n = 1$)

$(S/N)_n$ = value of signal-to-noise ratio per pulse required to produce same probability of detection when n pulses are integrated

23

Radar Cross Section



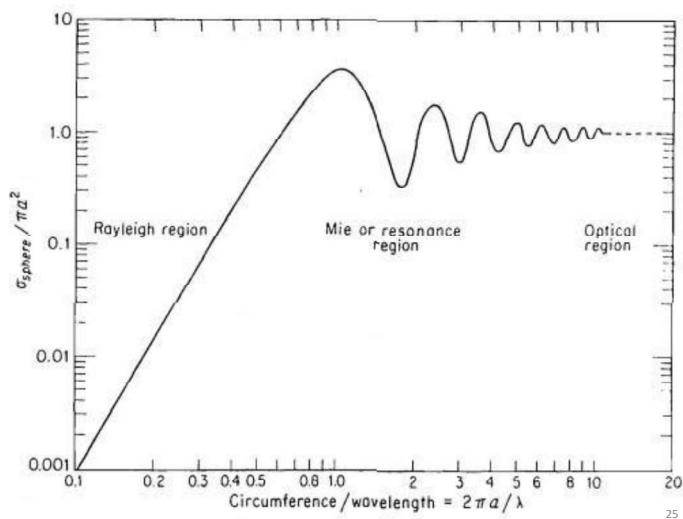
$$\sigma = \frac{\text{power reflected toward source/unit solid angle}}{\text{incident power density}/4\pi} = \lim_{R \rightarrow \infty} 4\pi R^2 \left| \frac{E_r}{E_i} \right|^2$$

where R = distance between radar and target

E_r = reflected field strength at radar

E_i = strength of incident field at target

24



Transmitted Power



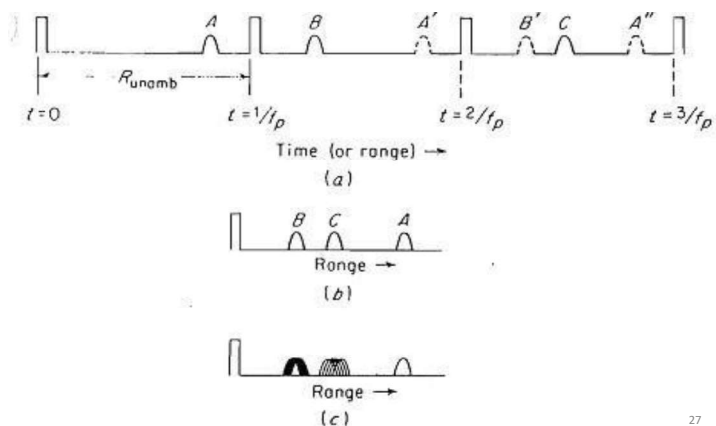
$$P_{av} = \frac{P_t \tau}{T_p} = P_t \tau f_p$$

$$R_{\max}^4 = \frac{P_{av} G A_e \sigma_n E_i(n)}{(4\pi)^2 k T_0 F_n(B_n \tau) (S/N)_1 f_p}$$

$$R_{\max}^4 = \frac{E_t G A_e \sigma_n E_i(n)}{(4\pi)^2 k T_0 F_n(B_n \tau) (S/N)_1}$$

26

Pulse Repetition Frequency



27

- Collapsing loss

$$L_i(m, n) = \frac{L_i(m+n)}{L_i(n)}$$

- Operator loss
- Field Degradation
- Propagation Effects



28

CONTENTS :: UNIT-II

- Doppler Effect
- CW Radar Block Diagram
- Isolation Between Transmitter and Receiver
- Non Zero IF Receiver
- Receiver Bandwidth Requirements
- Identification of Doppler Direction in CW Radar
- Applications of CW Radar
- CW Radar Tracking Illuminator

29

Doppler Effect

Separate antennas for transmission and reception help segregate the weak echo from the strong leakage signal

Doppler angular frequency ω_d given by

$$\frac{4\pi}{\lambda} \frac{dR}{dt} = \frac{4\pi v_r}{\lambda}$$

Where,

f_d = Doppler frequency shift

v_r = relative (or radial) velocity of target with to radar.

The Doppler frequency shift is $f_d = 2 * v_r / \lambda = 2 * v_r * f_0 / c$ where,

f_0 = transmitted frequency

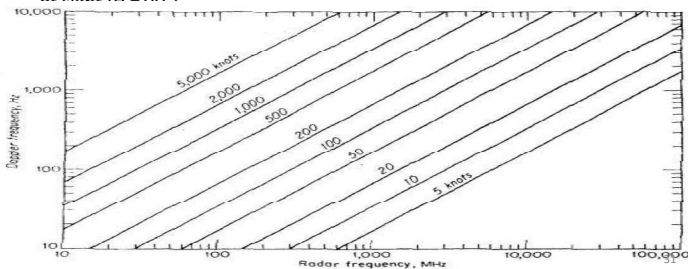
c = velocity of propagation = 3×10^8 m/s. If f_d is in

hertz v_r in knots, and λ in meters, $f_d = 1.03 * v_r / \lambda$

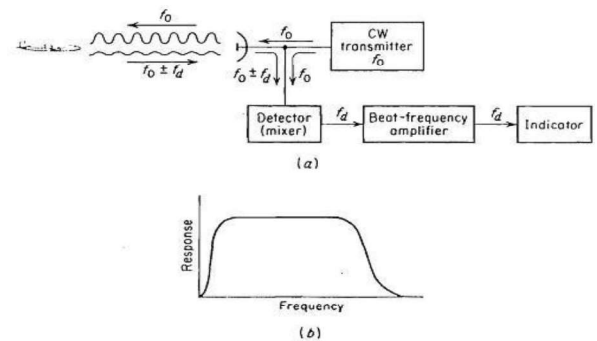
30

Doppler Effect

- The relative velocity may be written $v_r = v \cos \vartheta$, where v is the target speed and ϑ is the
- Angle made by the target trajectory and the line joining radar and target. When $\vartheta = 0$. The Doppler frequency is maximum.
- The Doppler is zero when the trajectory is perpendicular to the radar line of sight ($\vartheta = 90^\circ$)



CW Radar Block Diagram



32

Isolation Between Transmitter and Receiver

- Isolation between the transmitted and the received signals is achieved via separation in frequency as a result of the doppler effect.
- There are two practical effects which limit the amount of transmitter leakage power which can be tolerated at the receiver.
- (1) The maximum amount of power the receiver input circuitry can withstand before it is physically damaged or its sensitivity reduced
- (2) The amount of transmitter noise due to hum, microphonics etc.

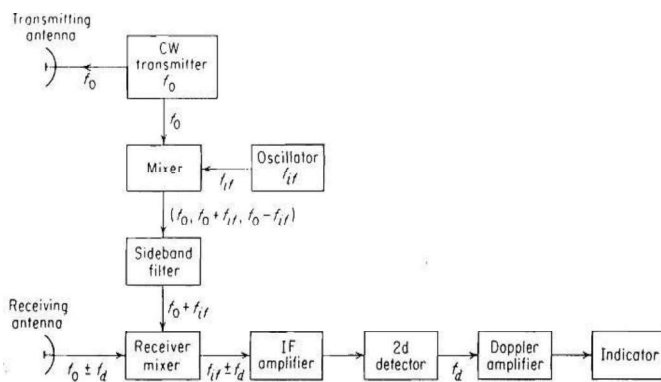
33

Isolation Between Transmitter and Receiver

- The amount of isolation which can be readily achieved between the arms of practical hybrid junctions such as the magic-T is of the order of 20 to 30 dB.
- Separate polarizations
- VSWR
- Separate antennas
- Dynamic cancellation of leakage

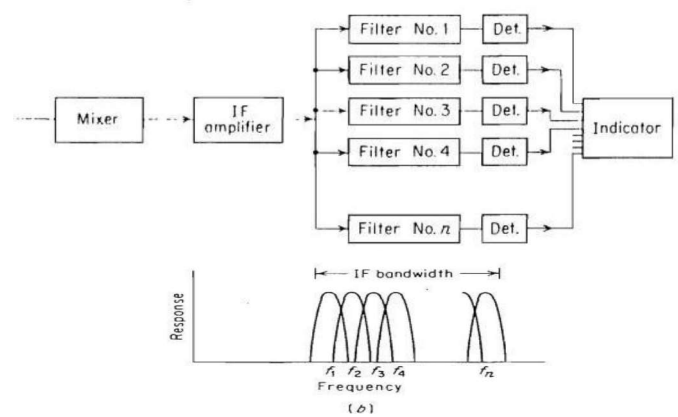
34

Non Zero IF Receiver



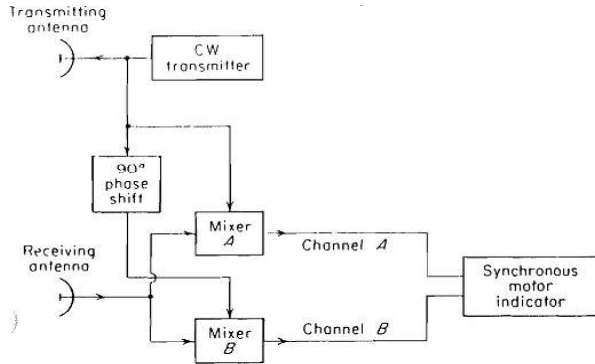
35

Receiver Bandwidth Requirements



36

Identification of Doppler Direction in



Identification of Doppler Direction in CW Radar

- The outputs from the two channels are

$$E_A (+) = K_2 E_0 \cos (wd t + \varphi)$$

$$E_B (+) = K_2 E_0 \cos (wd t + \varphi + \pi / 2)$$
- If the targets are receding (negative doppler), the outputs from the two channels are

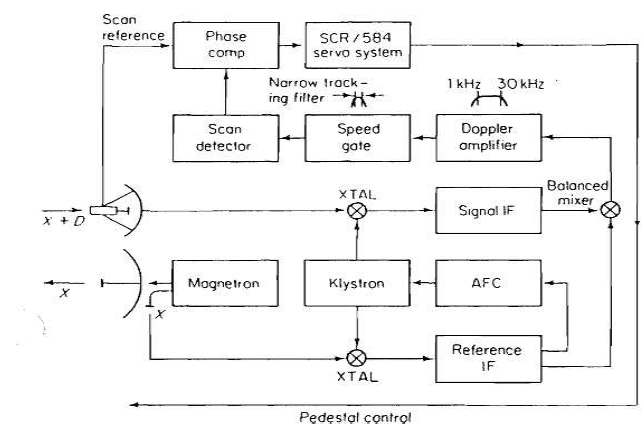
$$E_A (-) = K_2 E_0 \cos (wd t - \varphi)$$

$$E_B (-) = K_2 E_0 \cos (wd t - \varphi - \pi / 2)$$
- The direction of motor rotation is an indication of the direction of the target motion.

Applications of CW Radar

- Police speed monitor
- Collision avoidance.
- Control of traffic lights
- CW radar can be used as a speedometer to replace the conventional tachometer in Railways
- Warning of approaching trains.
- Speed of large ships.
- Velocity of missiles

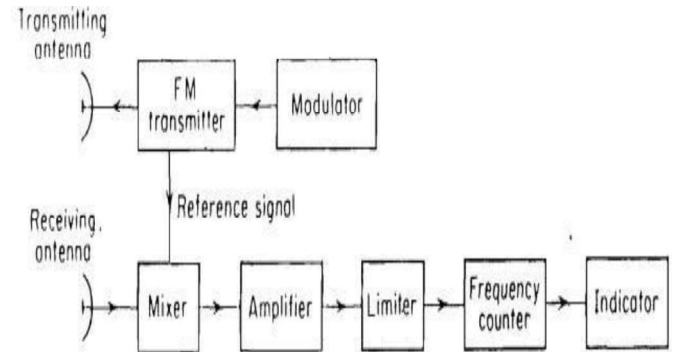
CW Radar Tracking Illuminator



FM-CW RADAR

- FMCW Radar
- Range and Doppler Measurement
- Approaching and Receding Targets
- FMCW Altimeter
- Measurement Errors
- Unwanted Signals
- Sinusoidal Modulation
- Multiple Frequency CW Radar

FMCW Radar



41

42

Range and Doppler Measurement

- If the rate of change of the carrier frequency is f_0 , the beat frequency is

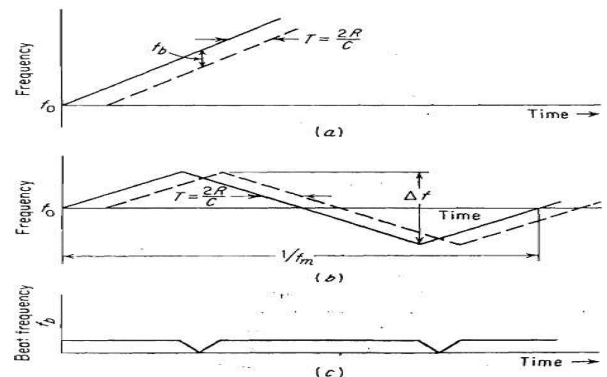
$$f_r = f_0 T = 2 R f_0 / c$$

- If the frequency is modulated at a rate f_m over a range Δf , the beat frequency is

$$f_r = 2 * 2 R f_m / c = 4 R f_m \Delta f / c$$

- Measurement of the beat frequency determines the range R .

$$R = c f_r / 4 f_m \Delta f$$

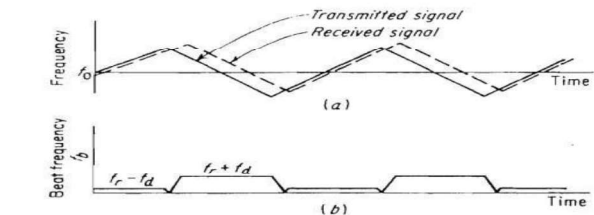


(a) Linear frequency modulation (b) triangular frequency modulation; (c) beat note of (b).

43

44

Range and Doppler Measurement



(a) Transmitted (solid curve) and echo (dashed curve)
(b) beat frequency

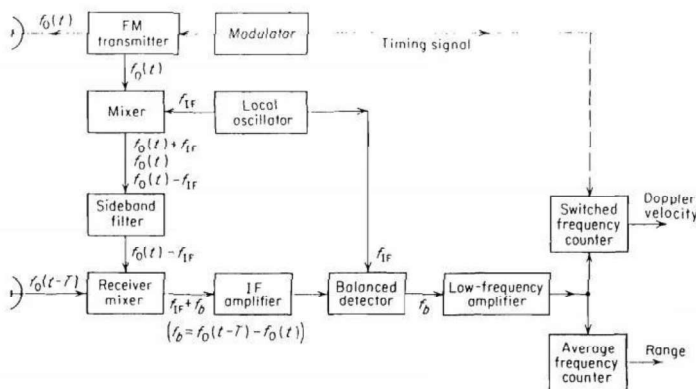
Approaching and Receding Targets

- FM cycle will be the difference between the beat frequency due to the range f_r , and the doppler frequency shift f_d
- $f_b(\text{up}) = f_r - f_d$
- $f_b(\text{down}) = f_r + f_d$
- The range frequency f_r , may be extracted by measuring the average beat frequency that is,
 - $f_r = 1/2[f_b(\text{up}) + f_b(\text{down})]$.
 - $f_d = 1/2[f_b(\text{up}) - f_b(\text{down})]$.
- $f_r > f_d$ Target Approaching
- $f_r < f_d$ Target Receding

45

46

FMCW Altimeter



47

Measurement Errors

- The average number of cycles N of the beat frequency f_b in one period of the modulation cycle f_m is $\overline{f_b} / f_m$, where the bar over, denotes time average.
- Which measures the number of cycles or half cycles of the beat during the modulation period.
- The total cycle count is a discrete- number since the counter is unable to measure fractions of a cycle.
- The discreteness of the frequency measurement gives rise to an error called the fixed error, or step error or quantization error

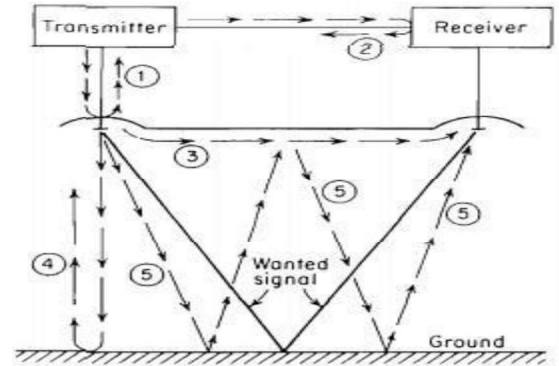
48

Measurement Errors

- $R = c N / 4 \Delta f$
- Where, R = range (altitude). m
- c = velocity of propagation. m/s Δf = frequency excursion. Hz
- Since the output of the frequency counter N is an integer, the range will be an integral multiple of $c / 4 \Delta f$ and will give rise to a quantization error equal to
- $\delta R = c / 4 \Delta f$
- $\delta R (m) = 75 / \Delta f (MHz)$

49

Unwanted Signals



50

Unwanted Signals



- The Unwanted signals include

 1. Transmitting Antenna impedance mismatch
 2. Receiver poor mixer match.
 3. Coupling between transmitter and receiver antennas
 4. The interference due to power being reflected back to the transmitter
 5. The double-bounce signal.

51

Sinusoidal Modulation

- If the CW carrier is frequency-modulated by a sine wave, the difference frequency obtained by heterodyning the returned signal with a portion of the transmitter signal may be expanded in a trigonometric series whose terms are the harmonics of the modulating frequency $\sin \left(2\pi f_0 t + \frac{\Delta f}{2f_m} \sin 2\pi f_m t \right)$
 - Assume the form where the transmitted signal be
- f_0 = carrier frequency
 f_m = modulation frequency
 Δf = frequency excursion

52

Sinusoidal Modulation

- The difference frequency signal may be

$$v_D = J_0(D) \cos(2\pi f_d t - \phi_0) + 2J_1(D) \sin(2\pi f_d t - \phi_0) \cos(2\pi f_m t - \phi_m) \\ - 2J_2(D) \cos(2\pi f_d t - \phi_0) \cos 2(2\pi f_m t - \phi_m) \\ - 2J_3(D) \sin(2\pi f_d t - \phi_0) \cos 3(2\pi f_m t - \phi_m) \\ + 2J_4(D) \cos(2\pi f_d t - \phi_0) \cos 4(2\pi f_m t - \phi_m) + 2J_5(D) \dots$$

where J_0, J_1, J_2 , etc = Bessel functions of first kind and order 0, 1, 2, etc., respectively

$$D = (\Delta f / f_m) \sin 2\pi f_m R_0 / c$$

R_0 = distance to target at time $t = 0$ (distance that would have been measured if target

were stationary)

c = velocity of propagation

f_d = doppler frequency shift

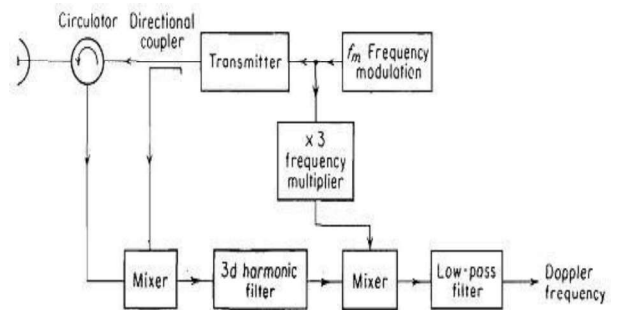
v_r = relative velocity of target with respect to radar

ϕ_0 = phase shift approximately equal to angular distance $2\pi f_0 R_0 / c$

ϕ_m = phase shift approximately equal to $2\pi f_m R_0 / c$

53

Sinusoidal Modulation (3rd Harmonic) Extraction



54

Multiple Frequency CW Radar

- The voltage waveforms of the two components of the transmitted signal v_{1r} and v_{2r} , may be written as

$$v_{1r} = \sin(2\pi f_1 t + \phi_1)$$

$$v_{2r} = \sin(2\pi f_2 t + \phi_2)$$

where ϕ_1 and ϕ_2 are arbitrary (constant) phase angles.

- The echo signal is shifted in frequency by the doppler frequency shift. The form of the doppler shifted

$$v_{1R} = \sin \left[2\pi(f_1 \pm f_{d1})t - \frac{4\pi f_1 R_0}{c} + \phi_1 \right]$$

$$v_{2R} = \sin \left[2\pi(f_2 \pm f_{d2})t - \frac{4\pi f_2 R_0}{c} + \phi_2 \right]$$

55

Multiple Frequency CW Radar



- Where, R_0 = range to target at a particular time $t = t_0$ (range that would be measured if target were not moving)
- f_{d1} = doppler frequency shift associated with frequency f_1
- f_{d2} = doppler frequency shift associated with frequency f_2
- Since the two RF frequencies f_1 , and f_2 are approximately the same the doppler frequency shifts f_{d1} and f_{d2} are approximately equal to one another. Therefore
- $f_{d1} = f_{d2} = f_d$

56

Multiple Frequency CW Radar

- The receiver separates the two components of the echo signal and heterodynes each received signal component with the corresponding transmitted waveform and

extra com |

$$v_{1D} = \sin \left(\pm 2\pi f_d t - \frac{4\pi f_1 R_0}{c} \right)$$

$$v_{2D} = \sin \left(\pm 2\pi f_d t - \frac{4\pi f_2 R_0}{c} \right)$$

57

Multiple Frequency CW Radar

- The phase difference between these two components is

$$\Delta\phi = \frac{4\pi(f_2 - f_1)R_0}{c} = \frac{4\pi \Delta f R_0}{c}$$

$$R_0 = \frac{c \Delta\phi}{4\pi \Delta f}$$

58

Multiple Frequency CW

- There is a limit to the value of Δf , since $\Delta\phi$ cannot be greater than 2π radians if the range is to remain unambiguous

- $R_{unamb} = c / 2\Delta f$
- Δf must be less than $c/2 R_{unamb}$
- When Δf is replaced with Pulse Repetition Rate gives Maximum Unambiguous Range of a Pulse Radar.

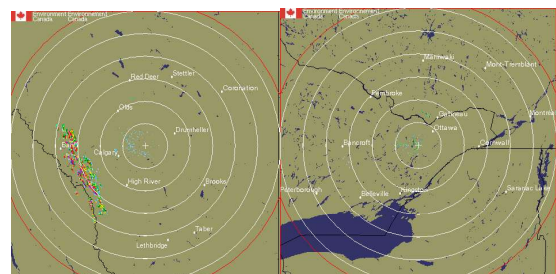
59

UNIT III

Moving Target Indicator Radar (MTI)

Clutter is the term used for radar targets which are not of interest to the user.

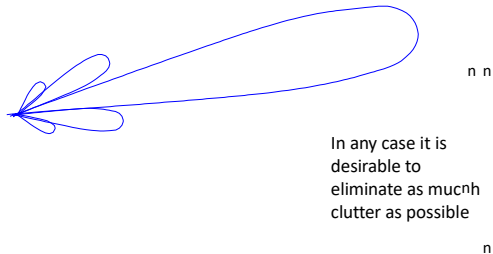
Clutter is usually caused by static objects near the radar but sometimes far away as well:



60

Moving Target Indicator Radar (MTI)

Sometimes clutter can be caused by sidelobes in the antenna pattern or a poorly adjusted antenna

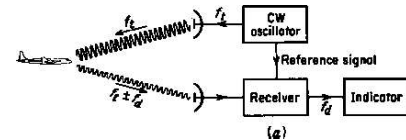


61

Moving Target Indicator Radar (MTI)

This is done by using the fact that the desired target is usually moving relative to the radar and thus causes a Doppler shift in the return signal.

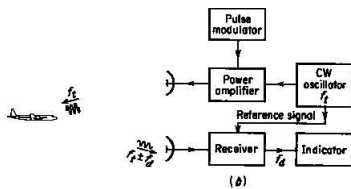
The Doppler shift can also be used to determine the relative speed of the target.



62

Moving Target Indicator Radar (MTI)

The simple CW example can be modified to incorporate pulse modulation



Note that the same oscillator is used transmission and demodulation of the return

Thus the return is processed **coherently**

i.e. the phase of the signal is preserved

63

Moving Target Indicator Radar (MTI)

The transmitted signal is

$$V_{ref} = A_2 \sin 2\pi f_t t$$

and the received signal is

$$V_{echo} = A_3 \sin \left[2\pi (f_t \pm f_d) t - \frac{4\pi f_t R_0}{c} \right]$$

these are mixed and the difference is extracted

$$V_{diff} = A_4 \sin \left[2\pi f_d t - \frac{4\pi f_t R_0}{c} \right]$$

This has two components, one is a sine wave at Doppler frequency, the other is a phase shift which depends on the range to the target, R_0

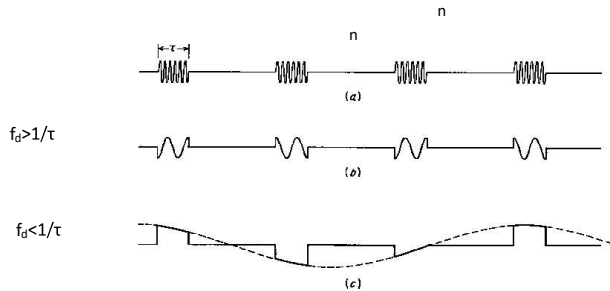
64

Moving Target Indicator Radar (MTI)

$$V_{diff} = A_4 \sin \left[2\pi f_d t - \frac{4\pi f_t R_0}{c} \right]$$

Note that for stationary targets $f_d = 0$ so V_{diff} is constant

Depending on the Doppler frequency one two situations will occur



65

Moving Target Indicator Radar (MTI)

Note that for a pulse width of $1\mu s$, the dividing line is a Doppler shift of 1 MHz.

If the carrier frequency is 1 GHz, this implies a relative speed of 30,000 m/s

Thus all terrestrial radars operate in a sampled mode and thus are subject to the rules of sampled signals

e.g. Nyquist's criterion

We shall also see that we can use Discrete Sample Processing (DSP) to handle some of the problems

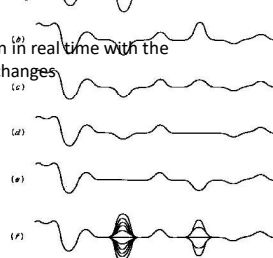
66

Moving Target Indicator Radar (MTI)

Looking at successive oscilloscope displays of radar receiver output we see:

At the ranges of the two targets, the return amplitude is varying as the radar samples the (relatively) slow Doppler signal.

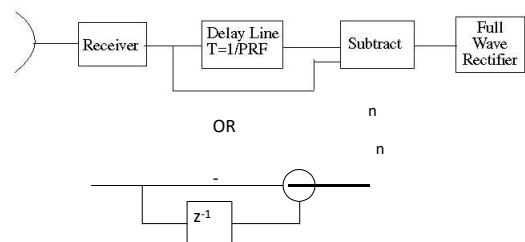
The bottom trace shows what would be seen in real time with the moving targets indicated by the amplitude changes



67

Moving Target Indicator Radar (MTI)

We usually want to process the information automatically. To do this we take advantage of the fact that the amplitudes of successive pulse returns are different:



68

Moving Target Indicator Radar (MTI)

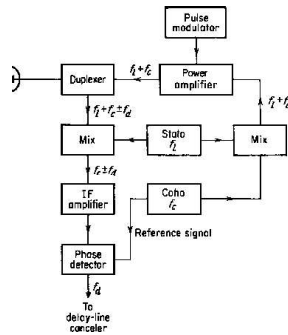
MTI Radar Block Diagrams

MOPA (master oscillator, power amplifier)

Power amplifiers: Klystron

TWT (Travelling wave tube) Solid State

(Parallel)



69

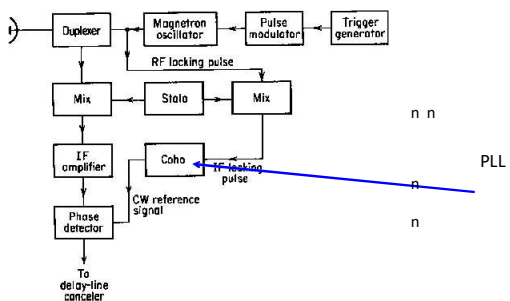
Moving Target Indicator Radar (MTI)

One of the problems with MTI in pulsed radars is that magnetrons are ON/OFF devices.

i.e. When the magnetron is pulsed it starts up with a random phase and is thus its output is not coherent with the pulse before it. Also it can not provide a reference oscillator to mix with the received signals.

Therefore some means must be provided to maintain the coherence (at least during a single pulse period)

Moving Target Indicator Radar (MTI)



71

Moving Target Indicator Radar (MTI)

The notes have a section on various types of delay line cancellers.

This is a bit out of date because almost all radars today

use digitized data and implementing the required delays is relatively trivial but it also opens up much more complex processing possibilities

70

72

Moving Target Indicator Radar (MTI)

The Filtering Characteristics of a Delay Line Cancellor

The output of a single delay canceller is:

$$v_1 - v_2 = 2k \sin \pi f_d T \cos \left[2\pi f_d \left(t - \frac{T}{2} \right) - \phi_0 \right]$$

This will be zero whenever $\pi f_d T$ is 0 or a multiple of π

The speeds at which this occurs are called the blindⁿ speeds of the radar

$$v_n = \frac{n\lambda f_p}{2} \quad \text{where } n \text{ is } 0, 1, 2, 3, \dots$$

73

Moving Target Indicator Radar (MTI)

If the first blind speed is to be greater than the highest expected radial speed the λf_p must be large

large λ means larger antennas for a given beamwidth

large f_p means that the unambiguous range will be quite small

So there has to be a compromise in the design of an MTI radar

n

n

n

74

Moving Target Indicator Radar (MTI)

The choice of operating with blind speeds or ambiguous ranges depends on the application

Two ways to mitigate the problem at the expense of increased complexity are:

- operating with multiple prfs
- operating with multiple carrier frequencies

n

n

n

n

75

Moving Target Indicator Radar (MTI)

Double Cancellation:

Single cancellers do not have a very sharp cutoff at the nulls which limits their rejection of clutter

(clutter does not have a zero width spectrum)

Adding more cancellers sharpens the nulls

n

n

n

n

76

Moving Target Indicator Radar (MTI)

Double Cancellation:

There are two implementations:

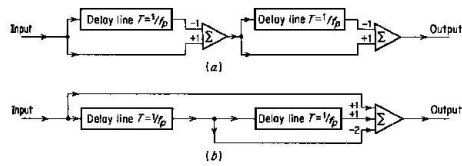


Figure 4.9 (a) Double-delay-line canceler; (b) three-pulse canceler.

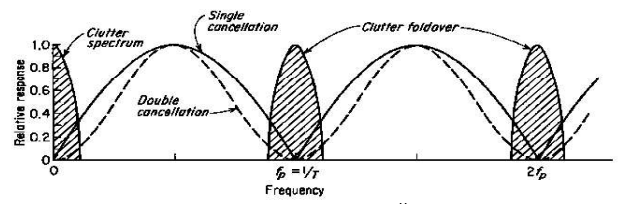
These have the same frequency response: which is the square of the single canceller response

$$|v| = 4\sin^2(\pi f_d T)$$

77

Moving Target Indicator Radar (MTI)

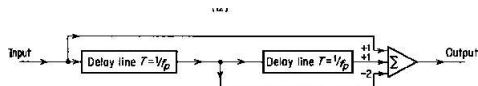
Double Cancellation:



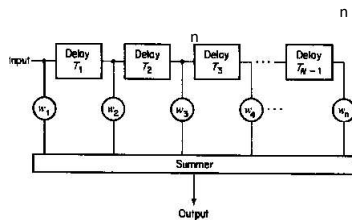
78

Moving Target Indicator Radar (MTI)

Transversal Filters



These are basically a tapped delay line with the taps summed at the output



79

Moving Target Indicator Radar (MTI)

Transversal Filters

To obtain a frequency response of $\sin^n \pi f_d T$, the taps must be binomially weighted i.e.

$$w_i = (-i)^{i-1} \frac{n!}{(n-i+1)!(i-1)!} ; i=1,2,3,\dots,n+1$$

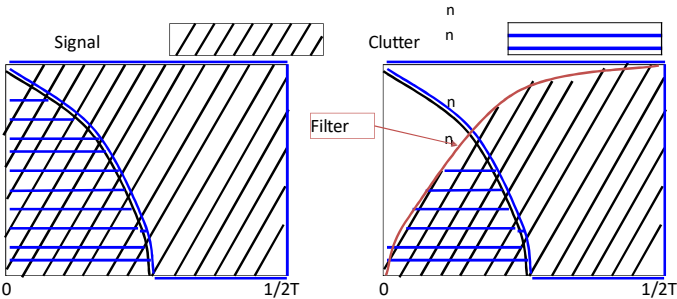
80

Moving Target Indicator Radar (MTI)

Filter Performance Measures
MTI Improvement Factor, I_C

$$I_C = \frac{(S/C)_{out}}{(S/C)_{in}}$$

Note that this is averaged over all Doppler frequencies



Moving Target Indicator Radar (MTI)

Filter Performance Measures
Clutter Attenuation, C/A

The ratio of the clutter power at the input of the canceler to the clutter power at the output of the canceler. It is normalized, (or adjusted) to the signal attenuation of the canceler, i.e. the inherent signal attenuation of the canceler is ignored

Moving Target Indicator Radar (MTI)

Transversal Filters with Binomial Weighting with alternating sign
Advantages:

Close to optimum for maximizing the Clutter improvement factor

Also close to maximizing the Clutter Attenuation

$$I_C = \frac{(S/C)_{out}}{(S/C)_{in}}$$

Moving Target Indicator Radar (MTI)

Transversal Filters with Binomial Weighting with alternating sign
Disadvantage:

As n increases the \sin^n filter cuts off more and more of the spectrum around DC and multiples of PRF
This leads to wider blind speed zones and hence loss of legitimate targets.

| % of targets rejected | n pulse canceler |
|-----------------------|--------------------|
| 20 | 2 |
| 35 | 3 |
| 48 | 4 |

Moving Target Indicator Radar (MTI)

The ideal MTI filter should reject clutter at DC and the PRFs but give a flat pass band at all other frequencies.

The ability to shape the frequency response depends to a large degree on the number of pulses used. The more pulses, the more flexibility in the filter design.

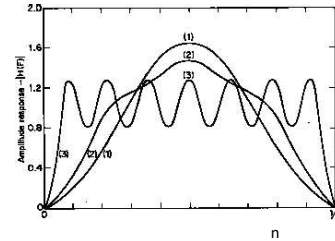
Unfortunately the number of pulses is limited by the scan rate and the bandwidth.

Note that not all pulses are useful:

The first $n-1$ pulses in an n pulse canceler are not useful

Moving Target Indicator Radar (MTI)

Some other transversal filter responses are shown:



(1) 3 pulse canceler

(2) 5 pulse "optimum" filter which maximizes I_c

(3) 15 pulse Chebyshev filter

85

86

Moving Target Indicator Radar (MTI)

Feed forward (finite impulse response or FIR) filters have only poles (one per delay)

More flexibility in filter design can be obtained if we use recursive or feedback filters (also known as infinite impulse response or IIR filters)

These have a zero as well as a pole per delay and thus have twice as many variables to play with

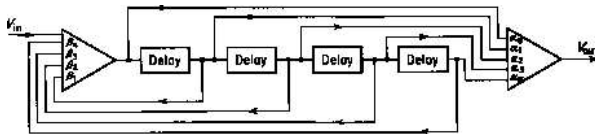
Moving Target Indicator Radar (MTI)

IIR filters can be designed using standard continuous-time filter techniques and then transformed into the discrete form using z transforms

Thus almost any kind of frequency response can be obtained with these filters.

They work very well in the steady state case but unfortunately their transient response is not very good. A large pulse input can cause the filter to "ring" and thus miss desired targets.

Since most radars use short pulses, the filters are almost always in a transient state



87

88

Moving Target Indicator Radar (MTI)

Multiple PRFs

An alternative is to use multiple PRFs because the blind speeds (and hence the shape of the filter response) depends on the PRF and, combining two or more PRFs offers an opportunity to shape the overall response.

89

Moving Target Indicator Radar (MTI)

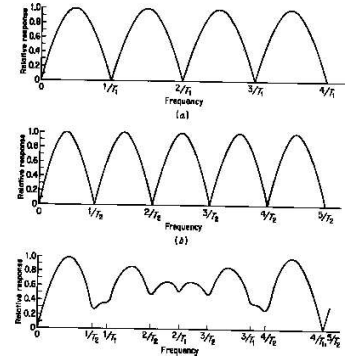
Multiple PRFs: Example

Two PRFs

Ratio 4/5

First blind speed is at

$5/T_1$ or $4/T_2$



90

Moving Target Indicator Radar (MTI)

Multiple PRFs: Example

Four PRFs

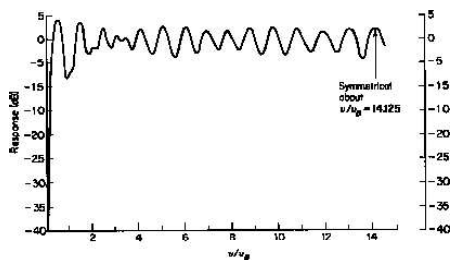
Ratio 25/30/27/31

First blind speed is at about

$28.25/T_{AV}$

where T_{AV}

is the average period of the four PRFs



91

Moving Target Indicator Radar (MTI)

Multiple PRFs: Example

Calculation of First Blind Speed

if the relationship between the Pulse Periods is

$$\frac{n_1}{T_1} = \frac{n_2}{T_2} = \dots = \frac{n_N}{T_N}$$

and v_B is the first blind speed of a PRF with average period

$$T_{AVE} = \frac{1}{N} [T_1 + T_2 + \dots + T_N]$$

The first blind speed is

$$v_1 = v_B \left[\frac{n_1 + n_2 + \dots + n_N}{N} \right]$$

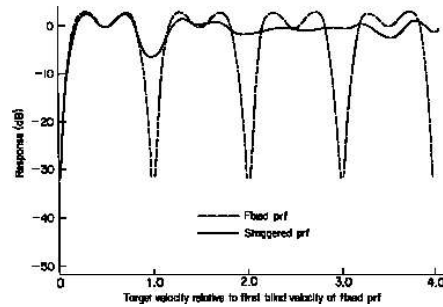
92

Moving Target Indicator Radar (MTI)

Multiple PRFs can also be used with transversal filters

Example

5 pulse canceler with 4 staggered PRFs



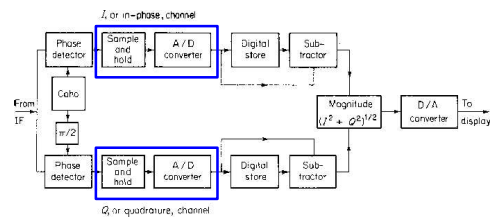
93

Moving Target Indicator Radar (MTI)

Digital (or Discrete) Signal Processing (DSP)

These days almost all radar signal processing is done using DSP.

The down-converted signal is sampled by an A/D converter as follows:



Note:

The quadrature channel removes blind phases

94

Moving Target Indicator Radar (MTI)

Advantages of DSP

- greater stability
- greater repeatability
- greater precision
- greater reliability
- easy to implement multiple PRFs
- greater flexibility in designing filters
- gives the ability to change the system parameters dynamically

95

Moving Target Indicator Radar (MTI)

Digital (or Discrete) Signal Processing (DSP)

Note that the requirements for the A/D are not very difficult to meet with today's technology.

Sampling Rate

Assuming a resolution (R_{res}) of 150m, the received signal has to be sampled at intervals of $c/2R_{res} = 1\mu s$ or a sampling rate of 1 MHz

Memory Requirement

Assuming an antenna rotation period of 12 s (5rpm) the storage required would be only 12 Mbytes/scan.

96

Moving Target Indicator Radar (MTI)

Digital (or Discrete) Signal Processing (DSP)

Quantization Noise

The A/D introduces noise because it quantizes the signal

The Improvement Factor can be limited by the quantization noise the limit being:

$$I_{QN} \approx 20 \log \left[(2^N - 1) \cdot 0.75 \right] \sqrt{\quad}$$

This is approximately 6 dB per bit

A 10 bit A/D thus gives a limit of 60 dB

In practice one or more extra bits to achieve the desired performance

97

Moving Target Indicator Radar (MTI)

Digital (or Discrete) Signal Processing (DSP)

Dynamic Range

This is the maximum signal to noise ratio that can be handled by the A/D without saturation

$$\text{dynamic_range} = 2^{2N-3} / k^2$$

N= number of bits

k=rms noise level divided by the quantization interval the larger k the lower the dynamic range

but $k < 1$ results in reduction of sensitivity

Note: A 10 bit A/D gives a dynamic range of 45.2dB

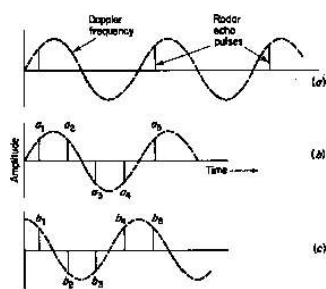
98

Moving Target Indicator Radar (MTI)

Blind Phases

If the prf is double the Doppler frequency then every other pair of samples can be the same amplitude and will thus be filtered out of the signal.

By using both inphase and quadrature signals, blind phases can be eliminated



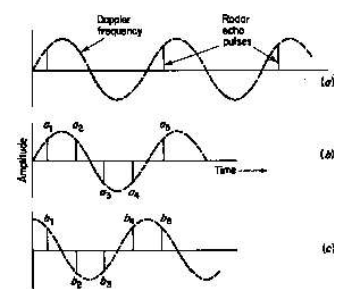
99

Moving Target Indicator Radar (MTI)

Blind Phases

If the prf is double the Doppler frequency then every other pair of samples can be the same amplitude and will thus be filtered out of the signal. (loss of 2.8dB and 13.7dB for P_d of 0.5 and 0.9 respectively)

By using both inphase and quadrature signals, blind phases can be eliminated

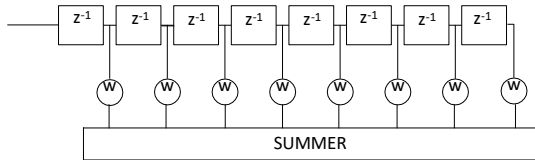


100

Moving Target Indicator Radar (MTI)

Digital Filter Banks and FFT

Example: Transversal Filter with 8 delay elements:



If the weights are set to:

$$w_{ik} = e^{-j[2\pi(i-1)k/N]}$$

$i=1,2,3,\dots,N$ and k is an index from 0 to $N-1$

101

Moving Target Indicator Radar (MTI)

The impulse response of this filter is:

$$h_k(t) = \sum_{i=1}^N \delta[t - (i-1)T] e^{-j2\pi(i-1)k/N}$$

And from the Fourier transform its frequency response is

$$H_k(f) = e^{-j2\pi fT} \sum_{i=1}^N e^{j2\pi(i-1)[fT - k/N]}$$

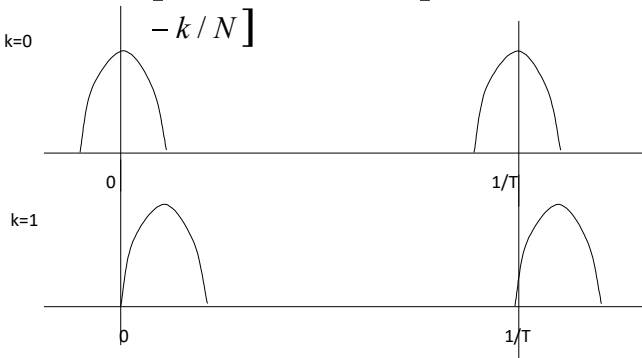
The magnitude of the response is

$$|H_k(f)| = \frac{\sin[\pi N(fT - k/N)]}{\sin[\pi(fT - k/N)]}$$

102

Moving Target Indicator Radar (MTI)

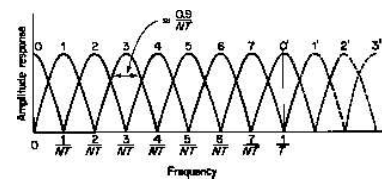
$$|H_k(f)| = \frac{\sin[\pi N(fT - k/N)]}{\sin[\pi(fT - k/N)]}$$



103

Moving Target Indicator Radar (MTI)

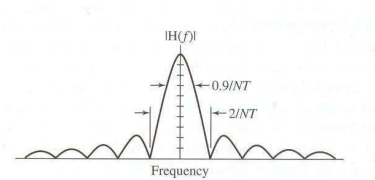
The response for all eight filters is:



104

Moving Target Indicator Radar (MTI)

The actual response for this filters is:



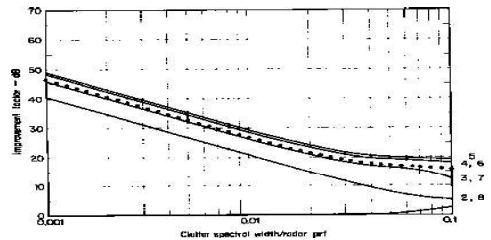
Which is $\sin(Nx)/\sin(x)$

The sidelobes of this filter are quite large (13dB below peak) and so it is not an ideal implementation

Moving Target Indicator Radar (MTI)

Other options are:

Uniform weighting and Chebyshev weights

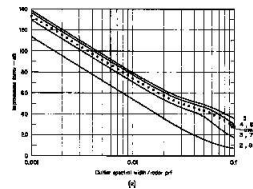


Clutter Improvement with Uniform weighting
(Filter Bank Only)

Moving Target Indicator Radar (MTI)

Filter Banks can also be preceded by cancelers

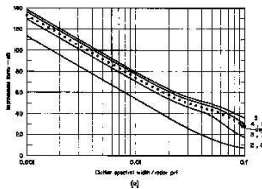
In the following cases a 3 pulse canceler is used



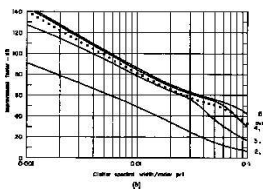
Moving Target Indicator Radar (MTI)

Filter Banks can also be preceded by cancelers

In the following cases a 3 pulse canceler is used ahead of an 8 pulse Doppler Filter Bank



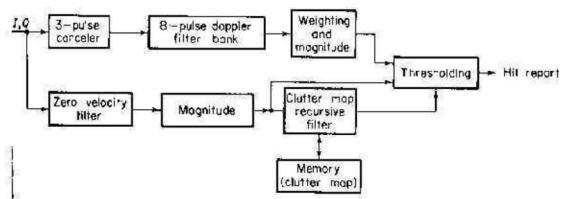
Uniform



Chebyshev

Moving Target Indicator Radar (MTI) MTD (Moving Target Detector)

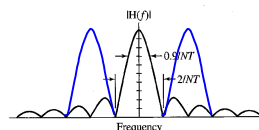
Example: ASR (Airport Surveillance Radar)



Moving Target Indicator Radar (MTI) MTD (Moving Target Detector)

Example: ASR (Airport Surveillance Radar)

After the filter bank the doppler filter outputs are weighted to reduce the effects of the sidelobes in the filter



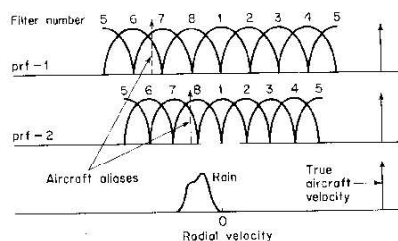
The outputs of the filters are modified by subtracting 25% of the outputs of the filters on either side.

109

110

Moving Target Indicator Radar (MTI) MTD (Moving Target Detector)

Example: ASR (Airport Surveillance Radar)



111

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Definitions:

• MTI Improvement Factor (I_C)

$$I_C = \frac{(S/C)_{out}}{(S/C)_{in}}$$

- Defined earlier

• Subclutter Visibility (SCV)

- The ratio by which a signal may be weaker than the coincident clutter and still be detected

• Clutter Visibility (CV)

- The Signal to Clutter ratio after filtering that provides the specified P_d and P_{fa} .

112

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Definitions:

• Clutter Attenuation

$$CA = (C_{IN} / C_{OUT})$$

- Defined earlier

• Cancellation Ratio

- The ratio by which a signal may be weaker than the coincident clutter and still be detected with the specified P_d and P_{fa} . All radial velocities

• Note

$$I_C = \left(\frac{C}{S} \right)_{IN} \cdot \left(\frac{S}{C} \right)_{OUT} = (SCV)(V_{OC})$$

113

Moving Target Indicator Radar (MTI) Limitations of MTI

Equipment Instabilities: Performance

Changes in signal from pulse to pulse will result in apparent clutter Doppler shift

These changes can have many sources

- pulse to pulse change in amplitude
- pulse to pulse change in frequency
- pulse to pulse change in phase
- timing jitter
- Changes in pulse width
- Changes in oscillator frequency between Tx and Rx

114

Moving Target Indicator Radar (MTI) Limitations of MTI

Equipment Instabilities: Performance

Changes in signal from pulse to pulse will result in apparent clutter Doppler shift

These changes can have many sources

- pulse to pulse change in amplitude
- pulse to pulse change in frequency
- pulse to pulse change in phase
- timing jitter
- Changes in pulse width
- Changes in oscillator frequency between Tx and Rx

115

Moving Target Indicator Radar (MTI) Limitations of MTI

Equipment Instabilities: Performance

Example: Phase variation

$$g_1 = A \cos \omega t$$

g_1 and g_2 are successive pulses

$$g_2 = A \cos(\omega t + \Delta \phi)$$

for a stationary target

The output of the two pulse filter is

$$g_1(t) - g_2(t) = 2A \sin\left(\frac{\Delta \phi}{2}\right) \sin\left(\omega t + \frac{\Delta \phi}{2}\right) \approx A \Delta \phi \sin\left(\omega t + \frac{\Delta \phi}{2}\right)$$

Resulting in a minimum Improvement
Factor of

$$I = \frac{A^2}{(A \Delta \phi)^2} = \frac{1}{(\Delta \phi)^2}$$

116

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Equipment Instabilities:

$$I = \frac{A^2}{(A \Delta \phi)^2} = \frac{1}{(\Delta \phi)^2}$$

Note that if we need $I_c = 40\text{dB}$,

The pulse to pulse phase variation
has to be less than 0.01 rad
(0.6°)

Moving Target Indicator Radar (MTI) Limitations of MTI

Equipment Instabilities: Performance

Some examples of the effects of instability

| | | |
|-------------------------|-----------------------------------|--|
| Transmitter frequency | $(\pi \Delta f \tau)^{-2}$ | where Δf = interpulse frequency change |
| Stalo or coho frequency | $(2\pi \Delta f T)^{-2}$ | B = bandwidth |
| Transmitter phase shift | $(\Delta \phi)^{-2}$ | τ = pulse width |
| Coho locking | $(\Delta \phi)^{-2}$ | T = transmission time |
| Pulse timing | $\tau^2 / (\Delta t)^2 2B\tau$ | $\Delta \phi$ = interpulse phase change |
| Pulse width | $\tau^2 / (\Delta \tau)^2 2B\tau$ | Δt = timing jitter |
| Pulse amplitude | $(A / \Delta A)^2$ | $\Delta \tau$ = pulse width jitter |
| | | ΔA = interpulse amplitude change |

117

118

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Internal Fluctuation of Clutter:

Many sources of clutter are capable of motion of one sort or another (translation, oscillation)

Examples:

- Trees: leaves/branches oscillate with magnitude/frequency depending on the wind speed
- Vegetation: similar to trees (possibly less than trees)
- Sea: translational motion with variation in phase magnitude and
- Rain: translational motion with oscillation due to turbulence (thunderstorms)
- Chaff: similar to rain with higher magnitude

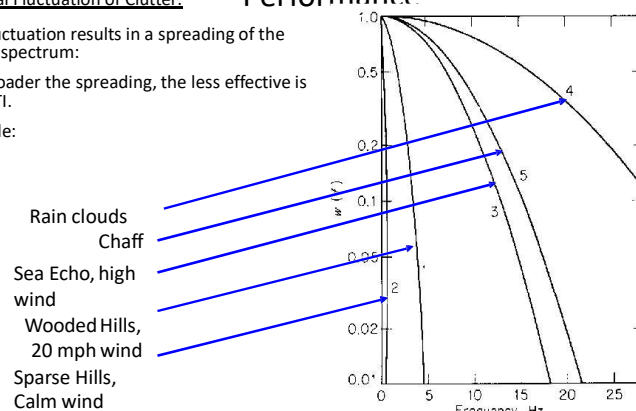
Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Internal Fluctuation of Clutter:

This fluctuation results in a spreading of the clutter spectrum:

The broader the spreading, the less effective is the MTI.

Example:



119

120

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Internal Fluctuation of Clutter:

The spectrum of clutter can be expressed mathematically as a function of one of three variables:

1. a , a parameter given by Figure 4.29 for various clutter types
2. σ_c , the RMS clutter frequency spread in Hz
3. σ_v the RMS clutter velocity spread in m/s

the clutter power spectrum is represented by $W(f)$

121

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Internal Fluctuation of Clutter:

The power spectra expressed in the three parameters are:

1. $W(f) = |g(f)|^2 = |g_0|^2 \exp \left[-a \left(\frac{f}{f_0} \right)^2 \right]$
2. $W(f) = W_0 \exp \left[-\frac{f^2}{2\sigma_c^2} \right]$
3. $W(f) = W_0 \exp \left[-\frac{f^2 \lambda^2}{8\sigma_v^2} \right]$

122

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Clutter Attenuation

The definition of Clutter Attenuation is:

$$CA = \frac{\int_{-\infty}^{\infty} W(f) df}{\int_{-\infty}^{\infty} W(f) |H(f)|^2 df}$$

The frequency response of a single delay line filter is

$$2\sin(\pi f_d T)$$

123

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Clutter Attenuation

The definition of Clutter Attenuation is:

$$CA = \frac{\int_{-\infty}^{\infty} W(f) df}{\int_{-\infty}^{\infty} W(f) |H(f)|^2 df}$$

The frequency response of a single delay line filter is

$$2\sin(\pi f_d T)$$

and the spectrum of the clutter in terms of frequency is

$$\exp(-f^2 / 2\sigma_c^2)$$

124

Moving Target Indicator Radar (MTI) Limitations of MTI

Clutter Attenuation

Performance

Then

$$CA = \frac{\int_0^{\infty} W_0(f) \exp[-f^2/2\sigma_c^2] df}{\int_0^{\infty} W_0 \exp[-f^2/2\sigma_c^2] 4 \sin(\pi f T)^2 df}$$

Simplifying

$$CA = \frac{f_p^2}{4\pi^2 \sigma_c^2}$$

125

Moving Target Indicator Radar (MTI) Limitations of MTI

Clutter Attenuation

Performance

Note that

$$\sigma_c = \frac{a}{\lambda} \quad \text{and} \quad a = \frac{c^2}{8\sigma_v^2}$$

Thus

$$CA = \frac{f_p^2 \lambda^2}{16\pi^2 \sigma_v^2}$$

and

$$CA = \frac{af_p^2}{2\pi^2 f_0^2}$$

In terms of the parameter a

126

Moving Target Indicator Radar (MTI) Limitations of MTI

Improvement Factor

Performance

Since the average gain of a two pulse canceler is 2.

$$I_{1c} = \frac{f_p^2}{2\pi^2 \sigma_c^2} = \frac{f_p^2 \lambda^2}{8\pi^2 \sigma_v^2} = \frac{af_p^2}{\pi^2 f_0^2}$$

And for the three pulse canceler it is 6

$$I_{2c} = \frac{f_p^4}{8\pi^4 \sigma_c^4} = \frac{f_p^4 \lambda^4}{128\pi^4 \sigma_v^4} = \frac{a^2 f_p^4}{2\pi^4 f_0^4}$$

In general

$$I_{NC} = \frac{2^{N_l}}{N_l!} \left(\frac{f_p}{2\pi \sigma_c} \right)^{2N_l}$$

127

Moving Target Indicator Radar (MTI) Limitations of MTI

Performance

Antenna Scanning Modulation

Since the antenna spends only a short time on the target, the spectrum of any target is spread even if the target is perfectly stationary:

The two way voltage antenna pattern is

$$G(\theta) = G_0 \exp \left[\frac{-2.776\theta^2}{\theta_B^2} \right]$$

Dividing numerator and denominator

$$S_a = G_0 \exp \left[\frac{-2.776 \left(\frac{\theta}{\dot{\theta}_s} \right)^2}{\left(\frac{\theta_B}{\dot{\theta}_s} \right)^2} \right]$$

128

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Antenna Scanning Modulation

Since

$$\frac{\theta}{\dot{\theta}_s} = t \quad \text{and} \quad \frac{\theta_B}{\dot{\theta}_s} = t_0 \quad (\text{time on target})$$

$$S_a = K \exp \left[\frac{-2.776 t^2}{t_0^2} \right]$$

Taking the Fourier Transform

$$S_a = K_1 \exp \left[\frac{-\pi^2 f^2 t_0^2}{2.776} \right]$$

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Antenna Scanning Modulation

Since this is a Gaussian function the exponent must be of the form

$$\frac{f^2}{2\sigma_f^2}$$

Thus

$$\frac{-\pi^2 f^2 t_0^2}{2.776} = \frac{f^2}{2\sigma_f^2}$$

and

$$\sigma_f = \frac{1.178}{\pi t_0} \quad (\text{voltage spectrum})$$

or

$$\sigma_s = \frac{\sigma_f}{\sqrt{2}} \quad (\text{power spectrum})$$

or

$$\sigma_s = \frac{1}{3.77 t_0}$$

129

130

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Antenna Scanning Modulation

Substituting into the equations for I_c ,

$$I_{1s} = \frac{n_B^2}{1.388} \quad I_{2s} = \frac{n_B^4}{3.853}$$

Tracking with Scanning Radars (Track While scan)

Automatic Detection and Tracking (ADT)

Pure tracking radars use pencil beam antennas to determine the azimuth, elevation and range of a single target

Digital processing allows a surveillance radar to track many targets and also permits prediction of the target positions in the future which assists in collision avoidance.

Functions performed by ADT are:

- Detection
- Track initiation
- Track Association
- Track update
- Track smoothing
- Track termination

131

132

Tracking with Scanning Radars (Track While scan) Automatic Detection and Tracking (ADT)

Target Detection (Range)

As described before, the range is divided into range cells or "bins" whose dimensions are close to the resolution of the radar.

Each cell has a threshold and if a predetermined number of pulses exceed the threshold a target is declared present

Target Detection (Azimuth)

Resolution better than antenna beamwidth is obtained by seeking the central pulse in the n pulses and using the azimuth associated with that pulse.

Thus theoretically the resolution is

$$\frac{f_p}{360 \cdot 6 \cdot \omega}$$

133

Tracking with Scanning Radars (Track While scan) Automatic Detection and Tracking (ADT)

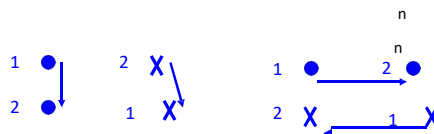
Track Initiation

Radar needs enough information to establish direction and speed of all targets present.

If only one target present, only two scans are required.

Usually require many scans to build up all of the tracks present

e.g. targets for two scans and two targets



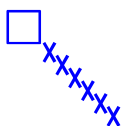
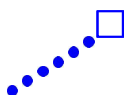
134

Tracking with Scanning Radars (Track While scan) Automatic Detection and Tracking (ADT)

Track Association

Radar attempts to associate each detection with an existing track

- establishes a search region (gate) for each established track,
- if detection falls inside gate, it is assumed to be associated with that track



n

n

135

Tracking with Scanning Radars (Track While scan) Automatic Detection and Tracking (ADT)

Track Association

Tradeoffs



Close tracks - small gate
Small gate: can lose target if it manoeuvres

Gate size is made variable depending on

- Accuracy of track
- Expected acceleration of the target

n

n

136

Tracking with Scanning Radars (Track While scan)

Automatic Detection and Tracking (ADT)

Track Smoothing

Predictions are based on track history

α - β Tracker

$$\hat{x}_n = x_{pn} + \alpha(x_n - x_{pn})$$

$$\hat{v}_n = v_{n-1} + \frac{\beta}{T_s}(x_n - x_{pn})$$

predicted measured

Predicted position:

$$x_{pn+1} = \hat{x}_n + \hat{v}_n T_s$$

137

UNIT -IV

TRACKING RADAR

138

1. Introduction

- Tracking radar systems are used to measure the targets range, azimuth angle, elevation angle, and velocity
- Predict the future values
- Target tracking is important to military and civilian purposes as missile guidance and airport traffic control

139

Target tracking

Targets are divided to two types:

- 1 Single target
- 2 Multiple targets

140

Single target

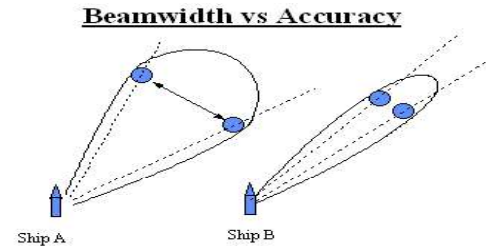
1 Angle tracking

- A- Sequential lobing
- B- Conical scan
- C- Amplitude compression monopulse
- D- Phase compression monopulse

2 Range tracking

Relation between beamwidth and accuracy

Antennas with wide beamwidth are less accuracy than antennas with narrow beam

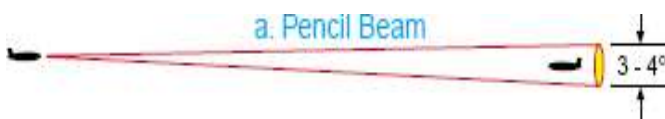


141

142

Pencil beam

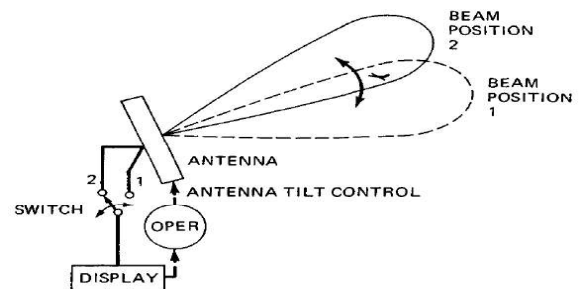
In tracking processes radar used narrower beams



143

Line of Sight (LOS) axis

The LOS is called the radar tracking axis too



144

Error signal

- Describes how much the target has deviated from the beam main axis
- Radar trying to produce a zero error signal
- Azimuth and elevation error

145

1. Sequential lobing

- Sequential lobing is often referred to as lobe switching or sequential switching
- Accuracy depends on the pencil beam width
- It is very simple to implement

146

SCR- 268



147

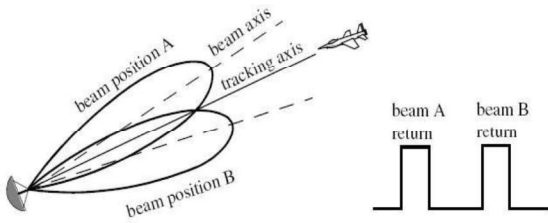
Concept of operation:

- Measuring the difference between the echo signals voltage levels

148

1- When the target being on the LOS

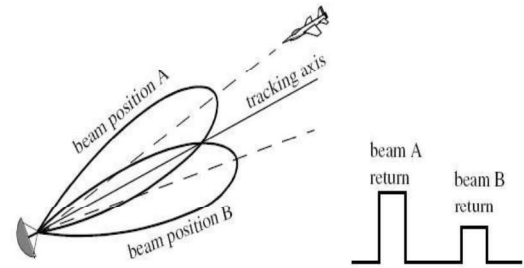
The difference between the echo signals voltage in (A) and (B) equal zero, that's mean zero error signal



149

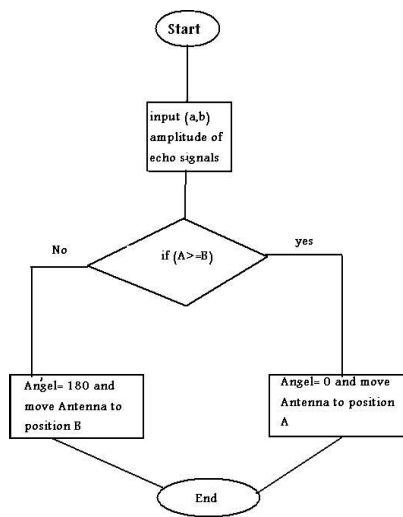
2. When the target being off the LOS

Signal in position(A) will attenuate more than signal in position(B) , that's mean a nonzero error signal



150

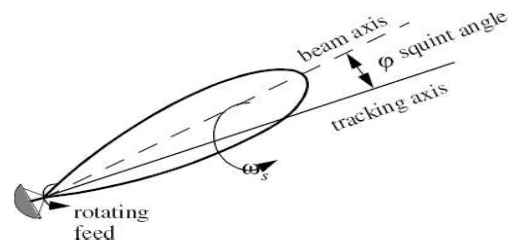
Mat lab Code



151

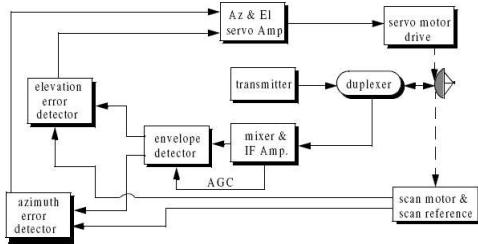
2. Conical scan

-It's an extension of sequential lobbing
-The feed of antenna is rotating around the antenna axis



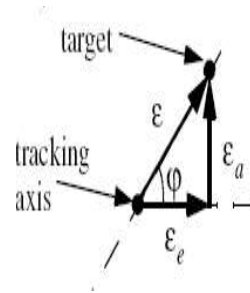
152

- The envelope detector is used to extract the return signal amplitude
- AGC is used to reduce the echo signal amplitude if it is strong and raises it when it is weaker



153

Elevation and azimuth error

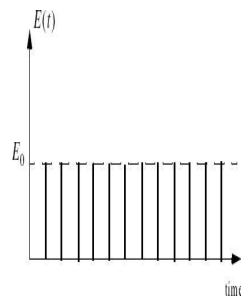
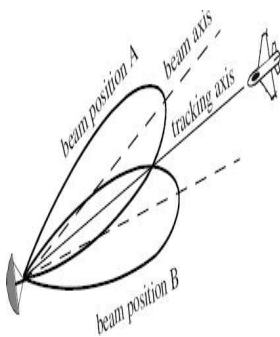


$$E_e(t) = -\frac{1}{2}E_0 \cos \phi$$

$$E_a(t) = \frac{1}{2}E_0 \sin \phi$$

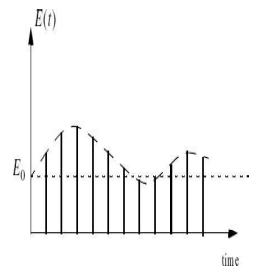
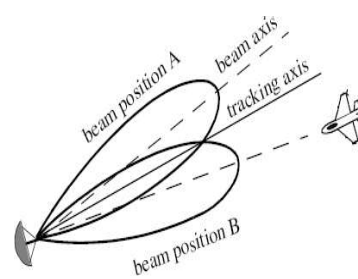
154

1- When the target being on the LOS



155

2. When the target being off the LOS



156

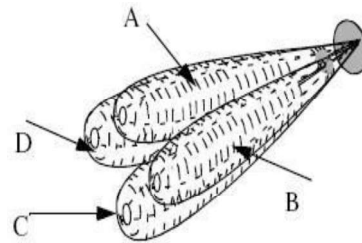
3. Amplitude compression monopulse

- This type is more accurate than sequential and conical scanning
- Feed generated four beams simultaneously with single pulse
- The four beams are inphase but have different amplitudes.

157

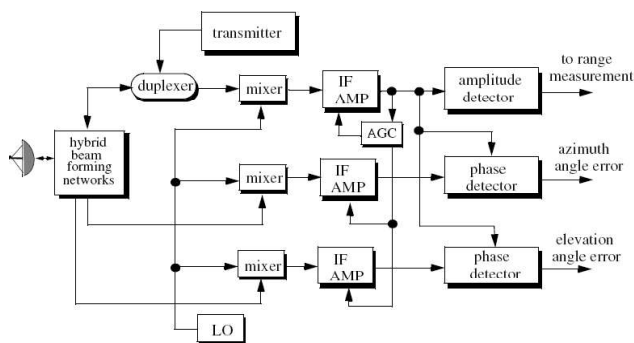
Four beams shape

Four feeds mainly horns are used to produce the monopulse antenna pattern



158

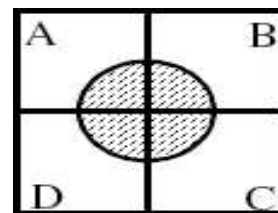
Simplified amplitude comparison monopulse radar block diagram



159

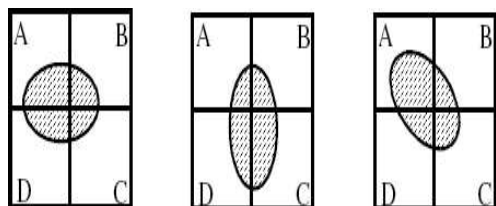
When the target being on the LOS

radar compares the amplitudes and phases of all echo signals of target



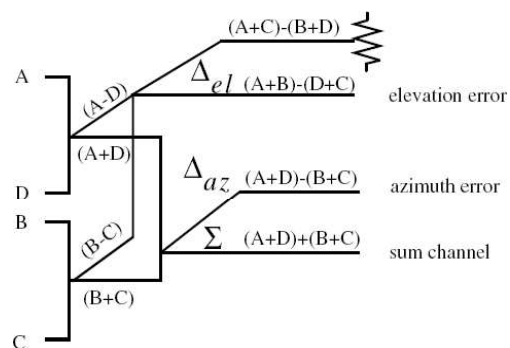
160

When the target being off the LOS



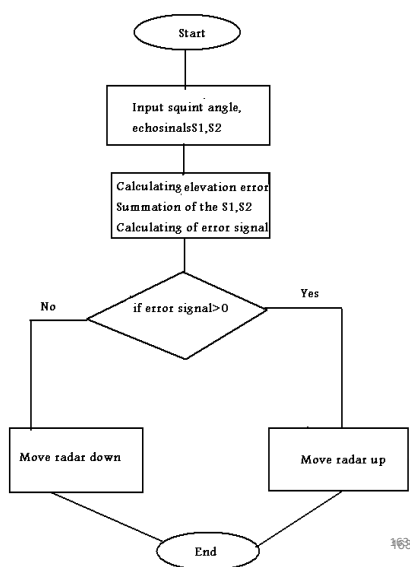
161

Microwave comparator circuitry



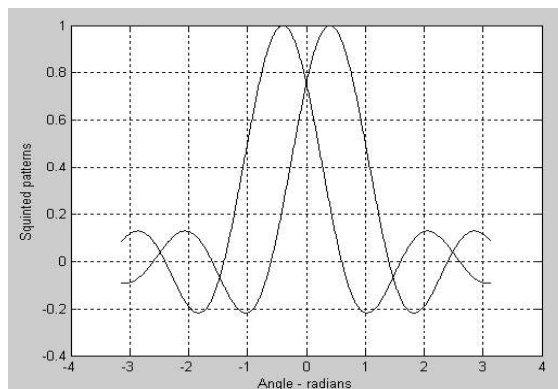
162

Mat lab code



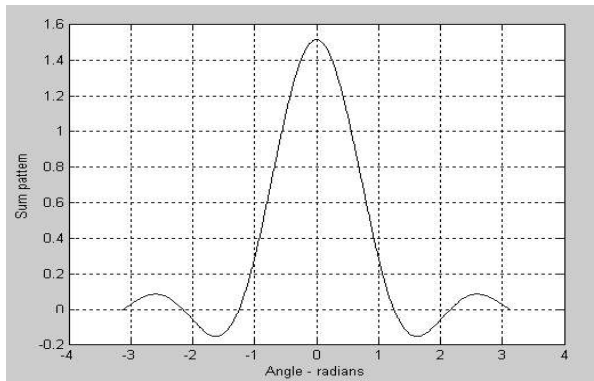
163

Two echo signals at squint angle (phi=0.4 rad)



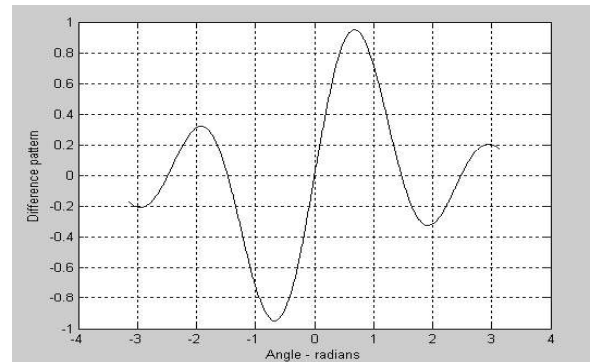
164

Sum of the two signals S1,S2



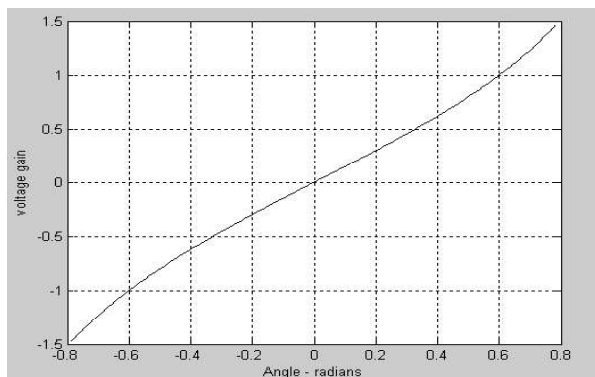
165

Difference between S1,S2



166

Elevation Error signal



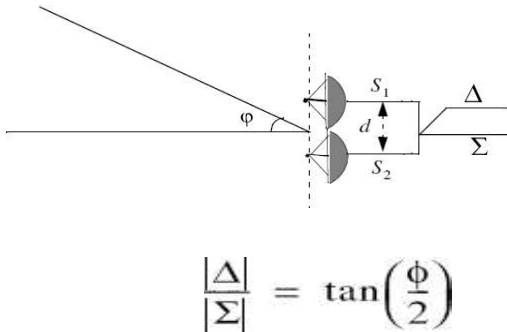
167

4- Phased compression monopulse

- It's the same as the last type but the amplitude here is equal for the four beams with different phases
- Phase comparison monopulse tracking radars use a minimum of a two-element array antenna

168

Single coordinate phase monopulse antenna



169

Range tracking

- Target range is measured by estimating the round-trip delay

$$R = \frac{c T_R}{2}$$

where $c = 3 \times 10^8, m/s$

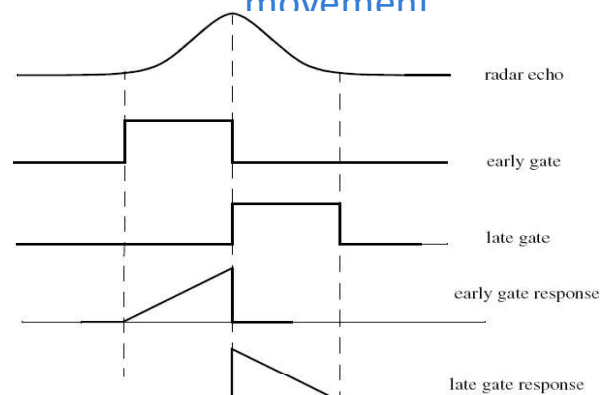
$T_R = \text{round-trip time, sec}$

170

Split Gate System

- It consist of two gates:
- 1-Early gate 2- Late gate
- The early gate produces positive voltage output but the late gate produces negative voltage output.
- Subtracting & integration
- Output is: zero, negative or positive

Split range gate - Its predict the target movement



171

172

Multiple Targets

Here the system is more difficult since:

- Tracking
- Scanning
- reporting

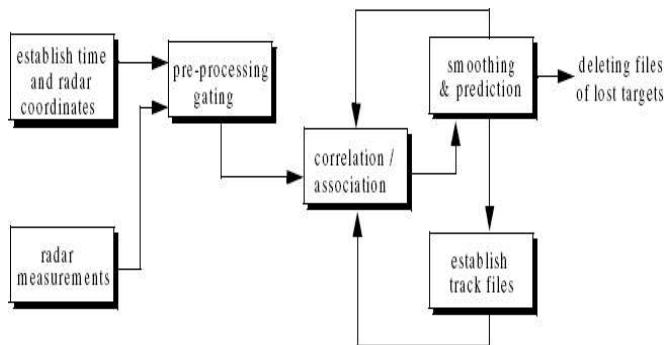
174

Track while scanning (TWS)

- This type of radar is used for multiple targets
- It scans for new targets while its tracking old targets
- When TWS scan a new target it initiates a new track file

175

Correlation unit is correlate old tracked file with a new scanned measurements



176

Any Two Radar Make

- Target detection
- Generation of tracking "Gates"
- Target track initiation and track file generation (if a new target)
- Correlation
- Track gate prediction, smoothing and positioning
- Display and future target calculations

177

Target Detection

This task is accomplished by two method :

- Circuit in receiver
- signal-processing equipment

178

Generation Gate

- Gate : small volume of space consist of many of cells
- Function : monitoring of each scan of the target information
- Gating has responsibility for knowing if new/exist target

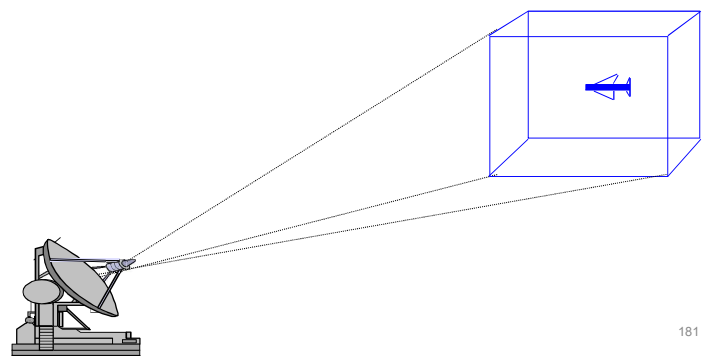
179

Gate Types

- Acquisition gate
- Tracking gate
- Turning gate

Acquisition Gate

- This gate is large to facilitate target motion cross one scan period



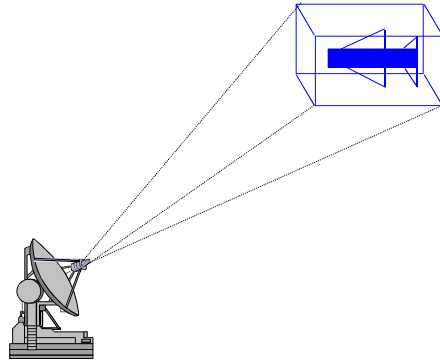
180

181

Tracking Gate

- This gate is generated when the target is within the acquisition gate on the next scan
- It is very small gate
- It is moving to the new expected target position

182

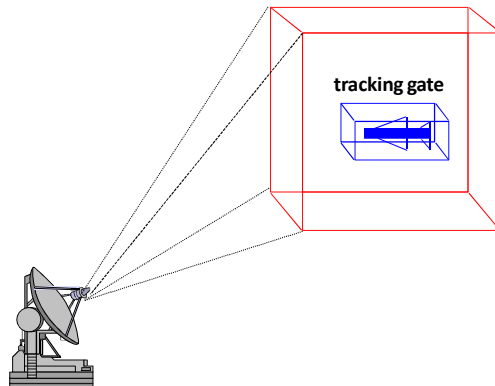


183

Turning gate

- It is generated if the observation within the tracking gate doesn't appear
- It has larger size than tracking gate
- Tracking gate included by it

184



185

Target track correlation and association

- All observations site on the boundary of tracking gate must be correlate with that track
- Each observation is compared with all track files
- Perhaps, observation is correlated with one track files ,several tracks or no tracks

186

Tracking Ambiguity Results

- If the observation correlates with more one track files, tracking ambiguity is appear.
- Two reasons cause this result:
 - 1 several targets site in the same gate
 - 2 several gates overlap on a single target

187

How To Solve Ambiguity?

- If the system designed so that an operator initiate the tracks, then solution by delete track
- But for the automatic systems , the solving by maintain software rules

188

Target track initiation and track file generation

- The track file is initiated when acquisition gate is generated
- Track file store position and gate data
- Each track file occupies position in the digital computer's high-speed memory
- Cont. refreshed data

189

Track gate prediction, smoothing and positioning

-Error Repositioning Smoothing

→ ←

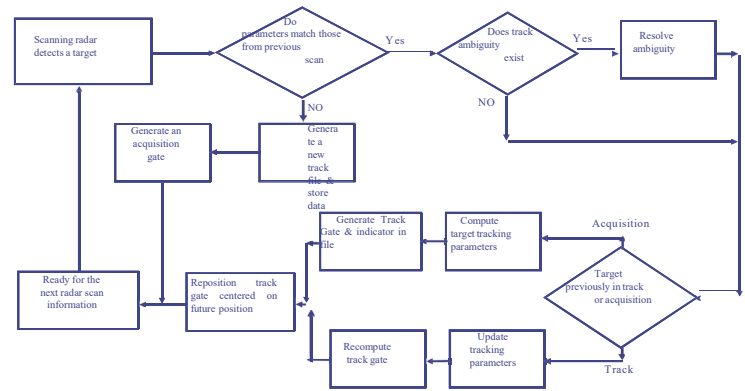
-The system lagged the target

-The system leading the target

-smoothing is completed by comparing predicted parameters with observed parameters

189

TWS System Operation



191

Conclusion

- We discussed the concepts of the different ways to determine the angle of a target and its range
- We show the different between single and multiple targets tracking
- We try to apply that on Matlab .

192

UNIT-V

Matched-Filter Receiver:

A network whose frequency-response function maximizes the output peak-signal- to-mean-noise (power) ratio is called a matched filter. This criterion, or its equivalent, is used for the design of almost all radar receivers

$$H(f) = G_s S^*(f) \exp(-j2\pi f t_1)$$

where $S(f) = \int_{-\infty}^{\infty} s(t) \exp(-j2\pi f t) dt$ = voltage spectrum (Fourier transform) of input signal

$S^*(f)$ = complex conjugate of $S(f)$

t_1 = fixed value of time at which signal is observed to be maximum

G_s = constant equal to maximum filter gain (generally taken to be unity)

$$|H(f)| \exp[-j\phi_s(f)] = |S(f)| \exp[j\phi_s(f) - 2\pi f t_1]$$

or

$$|H(f)| = |S(f)|$$

and

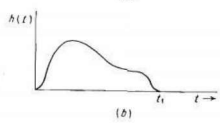
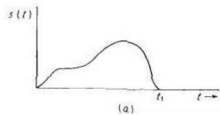
$$\phi_s(f) = -\phi_s(f) + 2\pi f t_1$$

192

Derivation of the matched-filter characteristic:

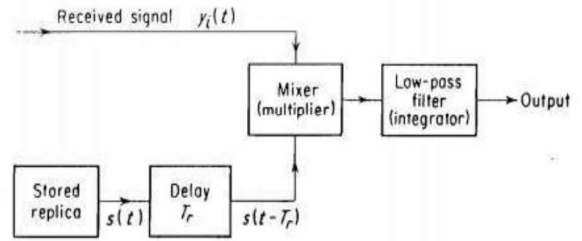
$$H(f) = G_p S^*(f) \exp(-j2\pi f t_1)$$

$$R_f = \frac{|s_m(t)|^2_{\max}}{N}$$



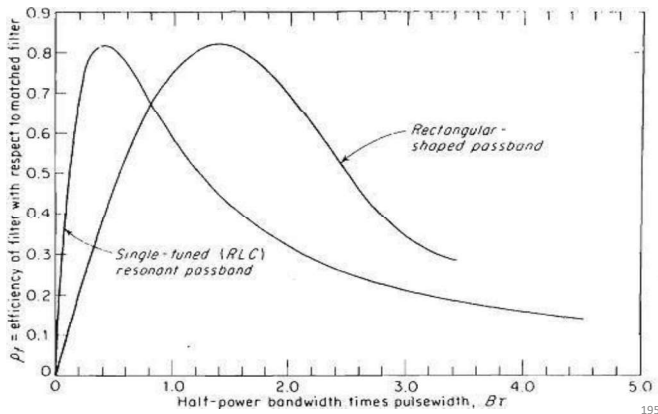
193

Correlation function and cross correlation receiver



194

EFFICIENCY OF NON-MATCHED FILTERS



195

| Input signal | Filter | Optimum $B\tau$ | Loss in SNR compared with matched filter, dB |
|-------------------|---------------------------------|-----------------|--|
| Rectangular pulse | Rectangular | 1.37 | 0.85 |
| Rectangular pulse | Gaussian | 0.72 | 0.49 |
| Gaussian pulse | Rectangular | 0.72 | 0.49 |
| Gaussian pulse | Gaussian | 0.44 | 0 (matched) |
| Rectangular pulse | One-stage, single-tuned circuit | 0.4 | 0.88 |
| Rectangular pulse | 2 cascaded single-tuned stages | 0.613 | 0.56 |
| Rectangular pulse | 5 cascaded single-tuned stages | 0.672 | 0.5 |

196

Matched filter with nonwhitenoise:

$$H(f) = \frac{G_s S^*(f) \exp(-j2\pi f t_1)}{[N_i(f)]^2}$$

$$H(f) = \frac{1}{N_i(f)} \times G_s \left(\frac{S(f)}{N_i(f)} \right)^* \exp(-j2\pi f t_1)$$

This indicates that the NWN matched filter can be considered as the cascade of two filters. The first filter, with frequency-response function $1/N_i(f)$, acts to make the noise spectrum uniform, or white. It is sometimes called the whitening filter. The second is the matched filter when the input is white noise and a signal whose spectrum is $S(f)/N_i(f)$.

197

Radar Receiver

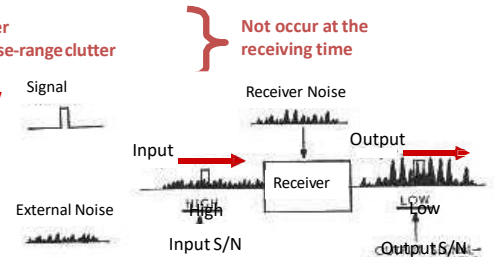


Leakage from the transmitter
Very strong echoes from close-range clutter

Pulse radars transmit a burst of energy and listen for echoes between transmissions.

The received signal is usually heavily corrupted by:

- Environmental noise
- Interference
- Noise from the radar system itself



198

Receiver Components

Antenna: Some radar antennas include low-noise amplifiers prior to forming the receive beams

Duplexer

Permits a single antenna to be shared between transmitter and receiver.

RF Filters

The receiver filters the signal to separate desired echoes from interference

Low Noise Amplifiers

Amplify the weak echo with minimum added noise

Mixer

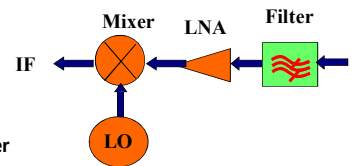
Down conversion

Oscillator

Protection components

Protect the receiver from high power transmitter

Receiver Front End



The radar *front end* consists of:
Bandpass filter or bandpass amplifier
LNA
Downconverter

The mixer itself and the preceding circuits are generally relatively broadband.

Tuning of the receiver, between the limits set by the **preselector or mixer bandwidth**, is accomplished by **changing the LO frequency**

199

200

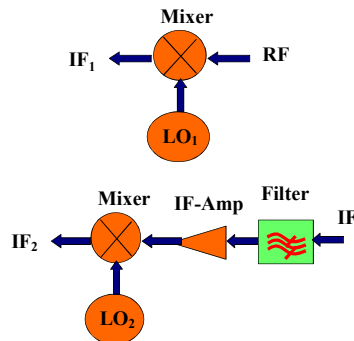
Superheterodyne principle is commonly used in radar receiver

More than one conversion step may be necessary to reach the final IF

IF range (0.1 and 100 MHz) without encountering serious image- or spurious-frequency problems in the mixing process.

At IF:
Amplification less costly
More stable than at microwave frequency
Simple filter operation

These advantages have been sufficiently powerful that competitive forms of receivers have virtually disappeared; only the superheterodyne receiver will be discussed in any detail.



Receiver Function

The function of a radar receiver is to amplify the echoes of the radar transmission and to filter them in a manner that will provide the maximum discrimination between desired echoes and undesired interference.

The interference comprises:

- Energy received from galactic sources
- Energy received from neighboring radars
- Energy received from neighboring communication systems
- Energy received from possibly jammers
- Noise generated in the radar receiver
- The portion of the radar's own radiated energy that is scattered by undesired targets (such as rain, snow, birds, and atmospheric perturbations)

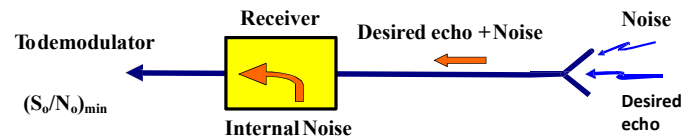
In airborne radars are used for altimeters or mapping:

- Ground is the desired target
- Other aircraft are undesired targets

More commonly, radars are intended for detection of

- Aircraft
- Ships
- Surface vehicles

Noise and Dynamic Range Considerations



Receivers **generate internal noise** which masks weak echoes being received from the radar transmissions. This noise is one of the fundamental limitations on the radar range

- ☐The receiver is often the most critical component
- ☐The purpose of a receiver is reliably recovering the desired echoes from a wide spectrum of transmitting sources, interference and noise
- ☐Noise is added into an RF or IF passband and degrades system sensitivity
- ☐Receiver should not be overloaded by strong signals

Noise Effects

Noise ultimately determines the threshold for the minimum echo level that can be reliably detected by a receiver.

The receiving system does not register the difference between signal power and noise power. The external source, an antenna, will deliver both signal power and noise power to receiver. The system will add noise of its own to the input signal, then amplify the total package by the power gain

Noise behaves just like any other signal a system processes

| | |
|---------------------|----------------------|
| Filters: | will filter noise |
| Attenuators: | will attenuate noise |

205

Thermal Noise

The most basic type of noise being caused by thermal vibration of bound charges. Also known as Johnson or Nyquist noise.



Available noise power $P_n = KTB$

Where, K = Boltzmann's constant ($1.38 \times 10^{-23} \text{ J/K}$)

T Absolute temperature in degrees Kelvin

B IF Band width in Hz

At room temperature 290 K:

For 1 Hz band width, $P_n = -174 \text{ dBm}$

For 1 MHz Bandwidth $P_n = -114 \text{ dBm}$

206

Shot Noise:

Source: random motion of charge carriers in electron tubes or solid state devices.

Noise in this case will be properly analyzed on based on noise figure or equivalent noise temperature

Generation-recombination noise:

Recombination noise is the random generation and recombination of holes and electrons inside the active devices due to thermal effects. When a hole and electron combine, they create a small current spike.

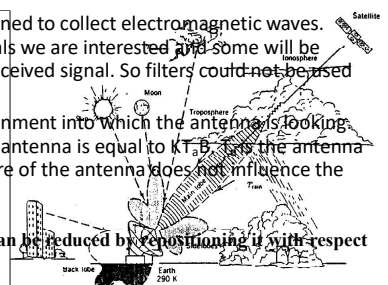
207

Antenna Noise

In a receiving system, antenna positioned to collect electromagnetic waves. Some of these waves will be the signals we are interested in and some will be noise at the same frequency of the received signal. So filters could not be used to remove such noise.

Antenna noise comes from the environment into which the antenna is looking. The noise power at the output of the antenna is equal to KT_aB , T_a is the antenna temperature. The physical temperature of the antenna does not influence the value of T_a .

The noise temperature of the antenna can be reduced by repositioning it with respect to sources of external noise

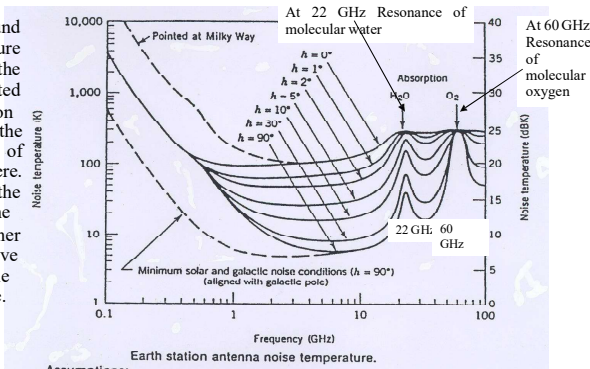


Antenna noise temperature pickup

$$T_A = \frac{1}{\Omega_A} \int_{4\pi} F(\theta, \varphi) \cdot T_B(\theta, \varphi) d\Omega$$

208

The background noise temperature increases as the antenna is pointed toward the horizon because of the greater thickness of the atmosphere. Pointing the antenna toward the ground further increases the effective loss, and hence the noise temperature.



Assumptions

- Antenna has no earth-looking sidelobes or a backlobe (zero ground noise)
- Antenna is lossless ■ h is antenna elevation angle (degrees)
- Sun not considered ■ Cool. temperate-zone troposphere

209

Equivalent Noise Temperature and Noise Figure

Noise Figure (F)



$$F = (S/N)_i / (S/N)_o$$

N_i = Noise power from a matched load at $T_o = 290$ K; $N_i = KT_o B$.

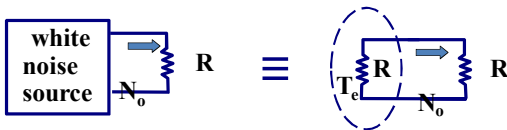
F is usually expressed in dB

$$F(\text{dB}) = 10 \log F$$

210

Equivalent Noise Temperature (T_e)

If an arbitrary noise source is white, so that its power spectral density is not a function of frequency, it can be modeled as equivalent thermal noise source and characterized by T_e .



$$T_e = N_o / KB,$$

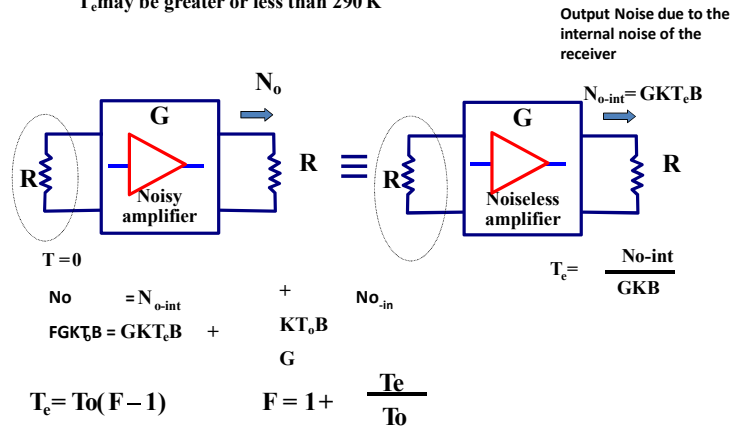
B is generally the bandwidth of the component or system

211

$$T_e \geq 0$$

If T_o is the actual temperature at the input port, usually 290 K

T_e may be greater or less than 290 K



212

Noise Figure of Cascaded Components



$$F_T = F_1 + \frac{F_2 - 1}{G_1} + \frac{F_3 - 1}{G_1 G_2} + \dots + \frac{F_n - 1}{G_1 G_2 \dots G_{n-1}}$$

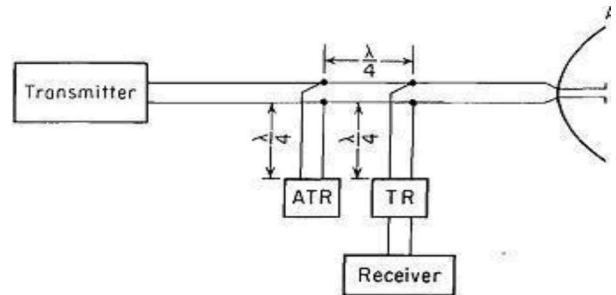
$$T_e = T_o(F - 1)$$

$$T_s = T_a + T_e \quad \longrightarrow \quad P_n = KT_s BG,$$

where, G is the overall gain of the system = $G_1 \times G_2 \times G_3 \dots \times G_n$

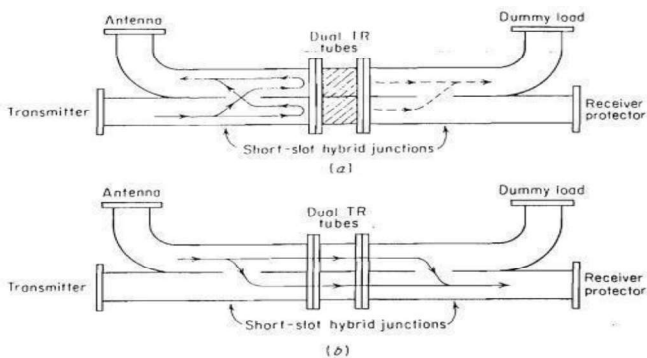
213

Branch-type duplexers



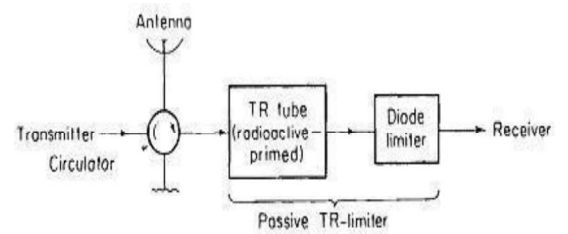
214

Balanced duplexer



215

Circulator and receiver protector



216

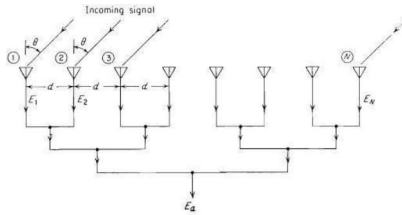
PHASED ARRAY ANTENNA

Radiation pattern for Phased array Antenna

$$E_a = \sin \omega t + \sin (\omega t + \psi) + \sin (\omega t + 2\psi) + \dots + \sin [\omega t + (N-1)\psi]$$

where ω is the angular frequency of the signal. The sum can be written

$$E_a = \sin \left[\omega t + (N-1) \frac{\psi}{2} \right] \sin \left(\frac{N\psi}{2} \right)$$



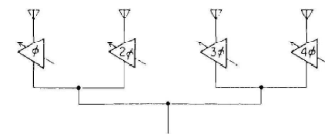
217

$$|E_a(\theta)| = \left| \frac{\sin [N\pi(d/\lambda) \sin \theta]}{\sin [\pi(d/\lambda) \sin \theta]} \right|$$

$$G_a(\theta) = \frac{|E_a|^2}{N^2} = \frac{\sin^2 [N\pi(d/\lambda) \sin \theta]}{N^2 \sin^2 [\pi(d/\lambda) \sin \theta]}$$

beam steering phased array antennas

$$G(\theta) = \frac{\sin^2 [N\pi(d/\lambda)(\sin \theta - \sin \theta_0)]}{N^2 \sin^2 [\pi(d/\lambda)(\sin \theta - \sin \theta_0)]}$$



218

Applications of phased array antennas

- ❖ Linear array with frequency scan
- ❖ Linear array with phase scan:
- ❖ Phase-frequency planar array:
- ❖ Phase-phase planar array

219

ADVANTAGES AND LIMITATIONS OF PHASED ARRAY ANTENNAS.

Limitations:

- The major limitation that has limited the widespread use of the conventional phased array in radar is its high cost, which is due in large part to its complexity.
- When graceful degradation has gone too far a separate maintenance is needed.
- When a planar array is electronically scanned, the change of mutual coupling that accompanies a change in beam position makes the maintenance of low side lobes more difficult.
- Although the array has the potential for radiating large power, it is seldom that an array is required to radiate more power than can be radiated by other antenna types or to utilize a total power which cannot possibly be generated by current high-power microwave tube technology that feeds a single transmission line.

220