

PPT
ON
RADAR SYSTEMS

B.Tech VI semester (IARE-R16)

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Unit I

FUNDAMENTALS 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

Radar History



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

Nature of radar



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

$$R = \frac{cT_R}{2}$$

- 1 Nautical mile=1.852 km

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

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

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

Radar Wave Forms



- Transmitted Power:: 1 Mega watt
- Pulse Width :: 1 Microsecond
- Pulse Repetition Period :: 1 Milli second

- Average Power can be calculated as

Transmitted Power * Pulse Width * Pulse Repetition Frequency

- Energy :: Transmitted Power * Pulse Width

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

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

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

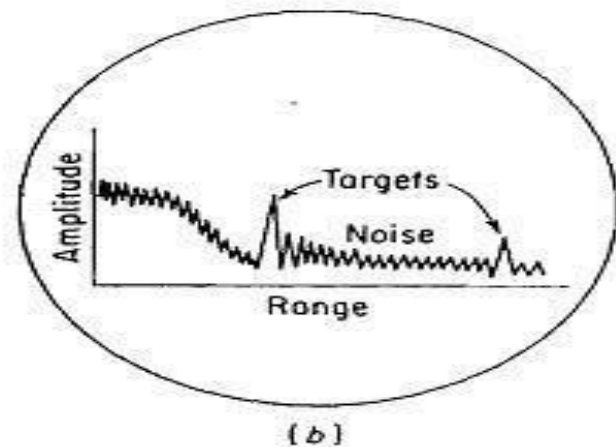
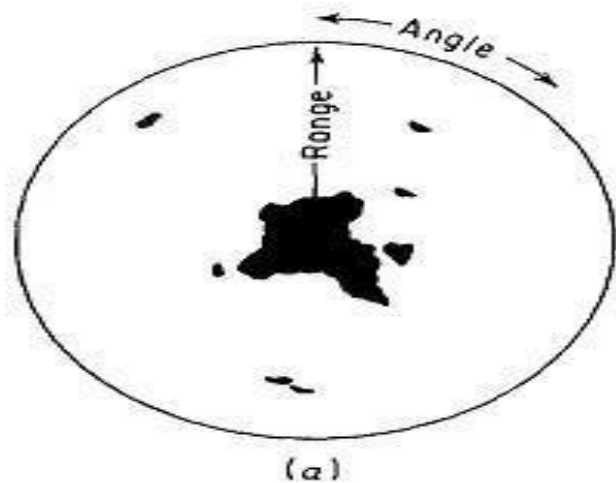
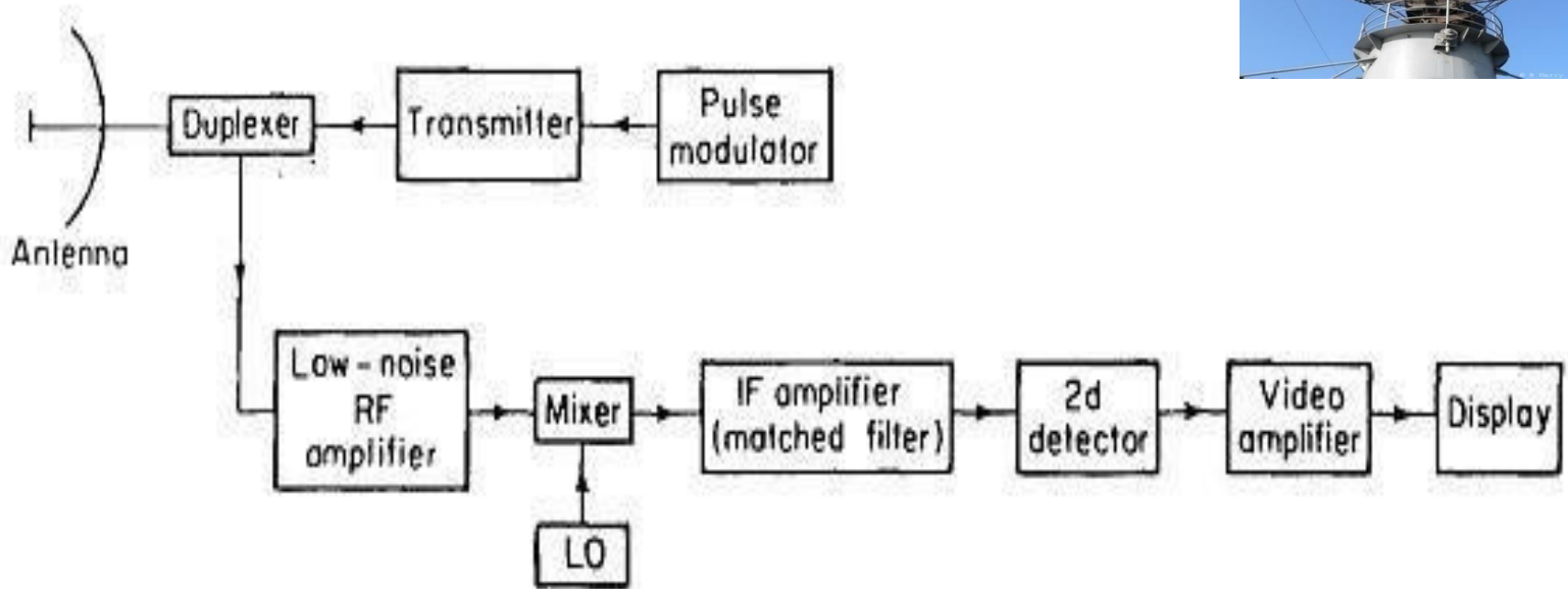
$$G = \frac{4\pi A_e}{\lambda^2}$$

- Two other forms of the radar

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

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

Radar Block Diagram



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	

Radar Applications



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

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

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 .

Minimum Detectable Signal

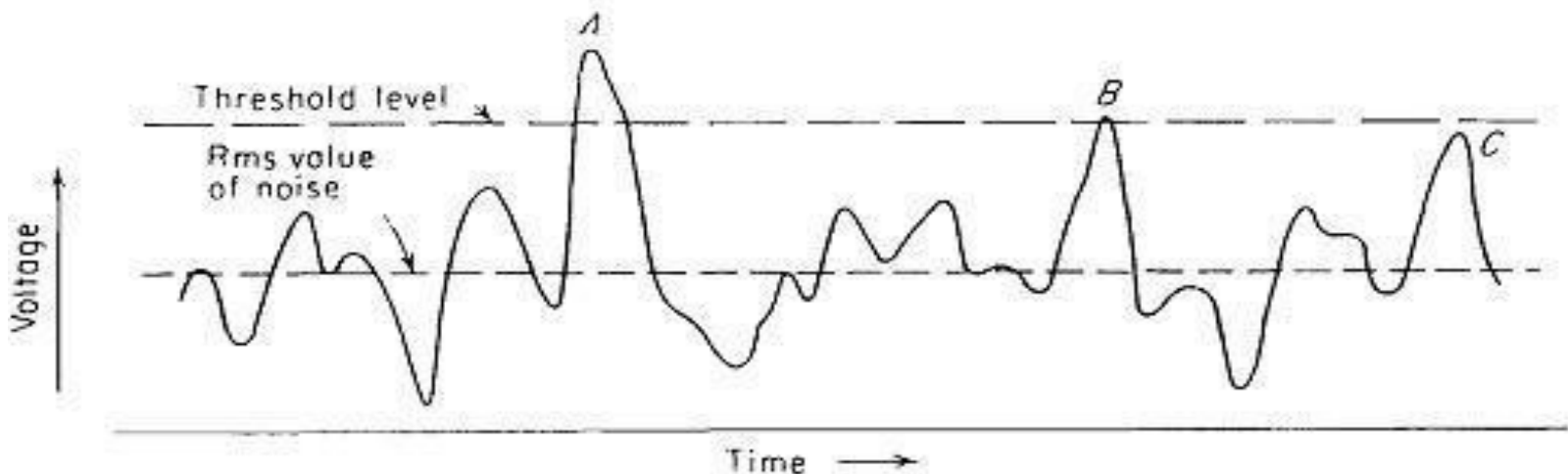


- The weakest signal the receiver can detect is called the minimum detectable signal.
- A matched filter for a radar transmitting a rectangular-shaped pulse is usually characterized by a bandwidth B approximately the reciprocal of the pulse width τ ,
or $B\tau \approx 1$
- Detection is based on establishing 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.

Minimum Detectable Signal



- Probability of Miss.
- Probability of False Alarm.



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

Receiver Noise and SNR



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

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

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

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

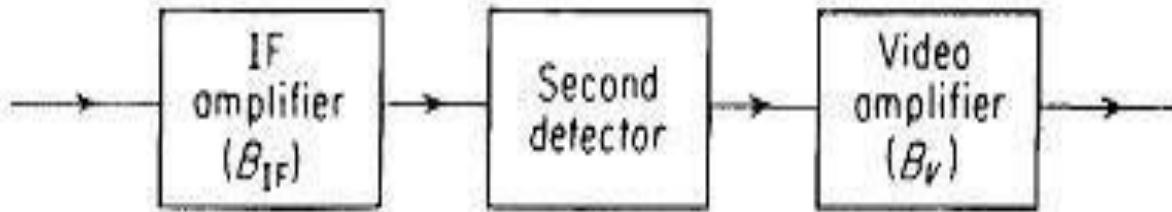
- If the minimum detectable signal S_{min} , is that value of S_i corresponding to the minimum ratio of output (IF) signal-to-noise ratio $(S_o/N_o)_{min}$ necessary for detection.

Receiver Noise and SNR



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

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



- The noise entering the IF filter (the terms filter and amplifier are used interchangeably) has a probability density function given by

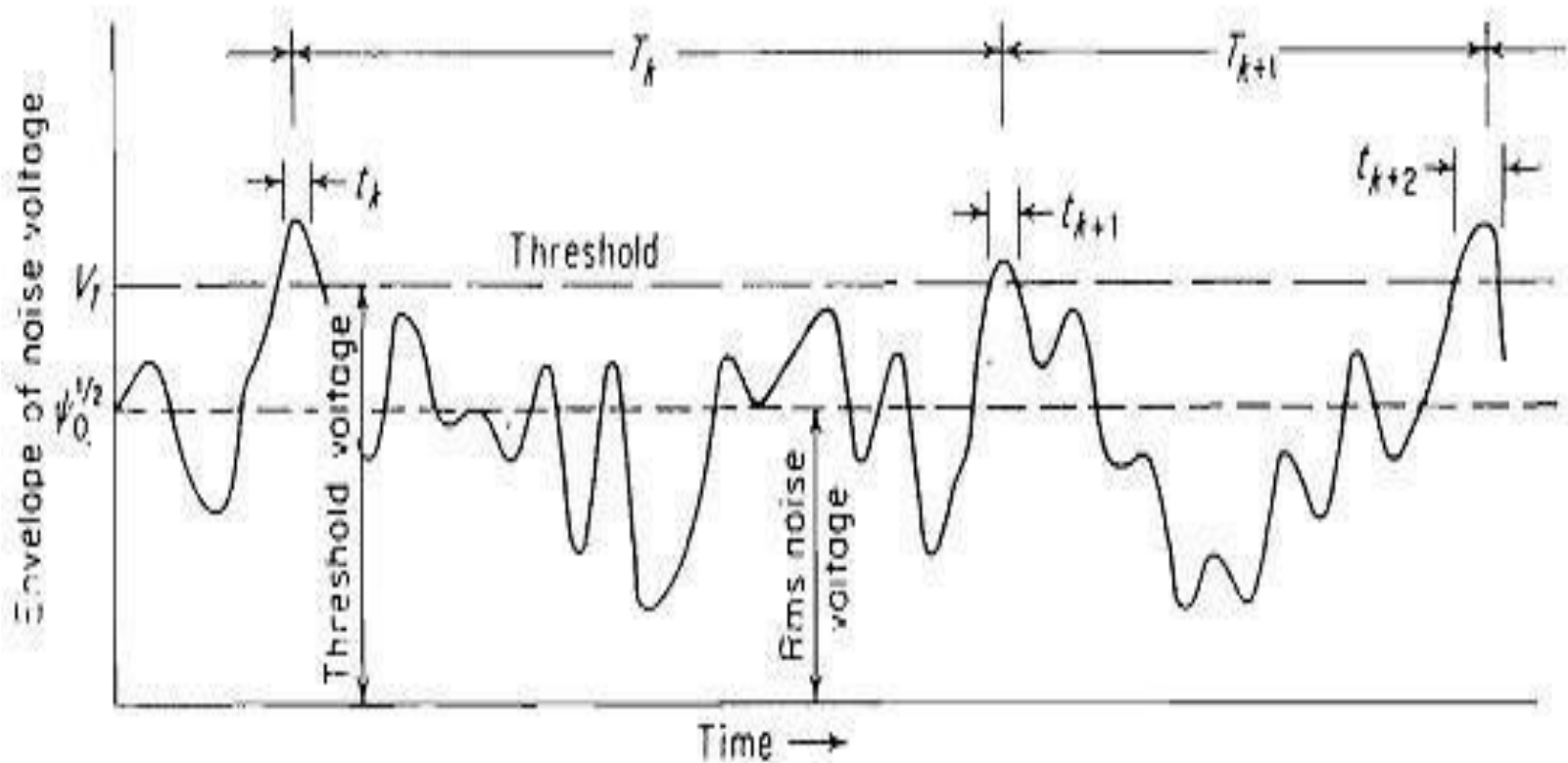
$$p(v) = \frac{1}{\sqrt{2\pi\psi_0}} \exp\left(-\frac{v^2}{2\psi_0}\right)$$

- 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 threshold V_T is

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



- The average time interval between crossings of the threshold by noise alone is denoted by the mean time T_{fa} ,

$$T_{fa} = \lim_{N \rightarrow \infty} \frac{1}{N} \sum_{k=1}^N T_k$$



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

- 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

Integration of Radar pulse



$$n_B = \frac{\theta_B f_p}{\dot{\theta}_s} = \frac{\theta_B f_p}{6\omega_m}$$

where θ_B = antenna beamwidth, deg

f_p = pulse repetition frequency, Hz

$\dot{\theta}_s$ = 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

Radar Cross Section

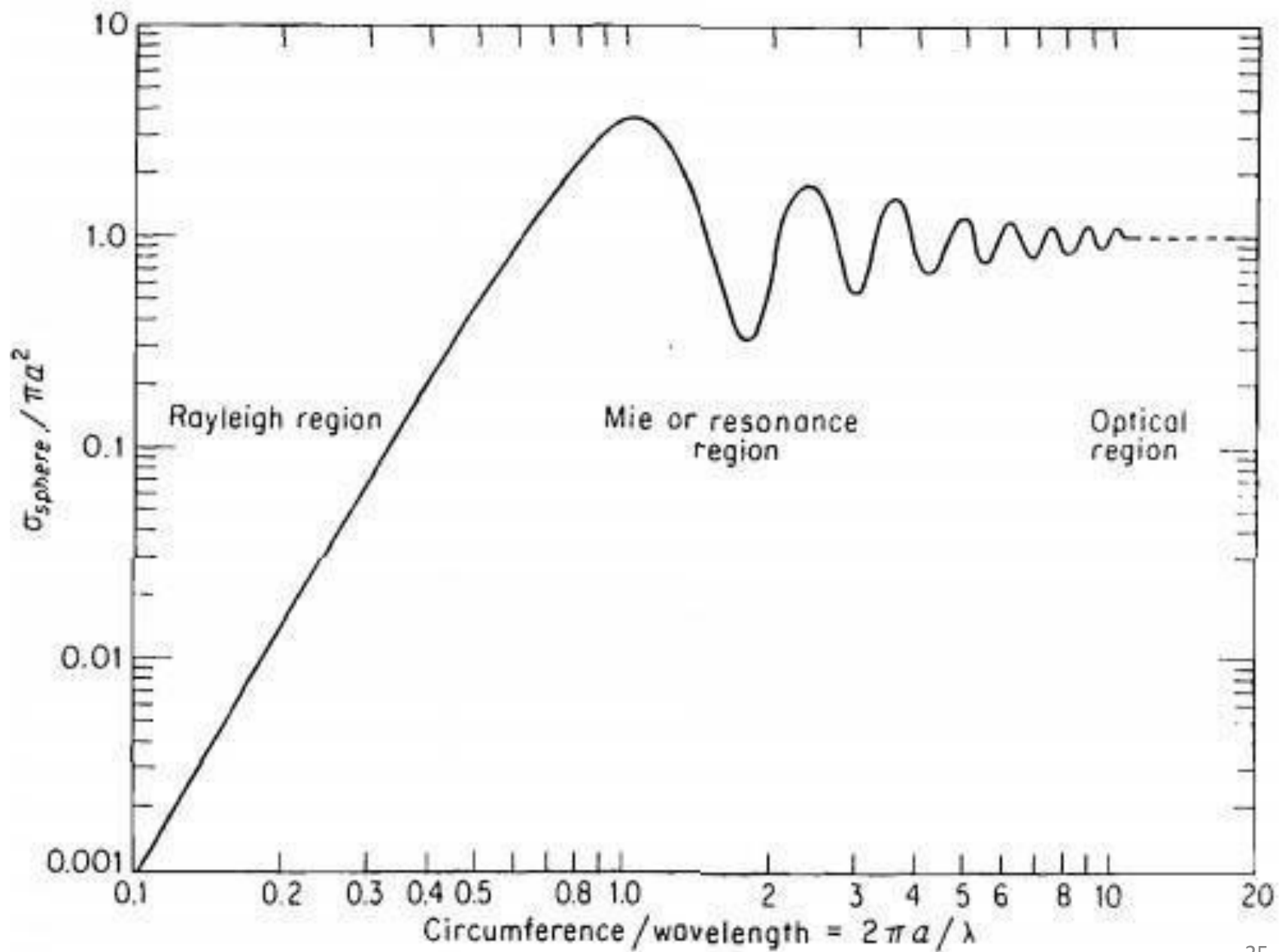


$$\sigma = \frac{\text{power reflected toward source/unit solid angle}}{\text{incident power density}/4\pi} = \lim_{R \rightarrow \infty} 4\pi R^2 \left| \frac{E_r}{E_i} \right|^2$$

where R = distance between radar and target

E_r = reflected field strength at radar

E_i = strength of incident field at target



Transmitted Power

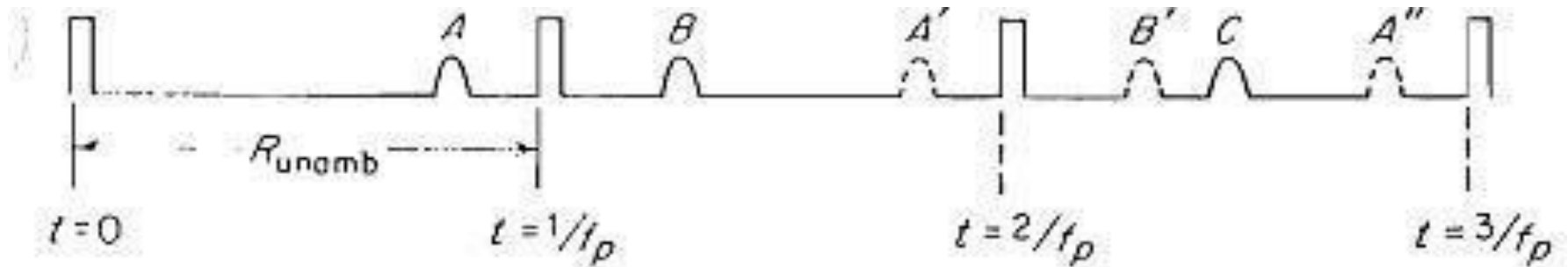


$$P_{av} = \frac{P_i \tau}{T_p} = P_i \tau f_p$$

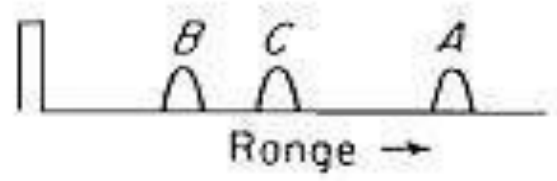
$$R_{max}^4 = \frac{P_{av} G A_e \sigma n E_i(n)}{(4\pi)^2 k T_0 F_n(B_n \tau) (S/N)_1 f_p}$$

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

Pulse Repetition Frequency



(a)



(b)



(c)



- Collapsing loss

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

- Operator loss
- Field Degradation
- Propagation Effects

Unit II

CW AND FREQUENCY MODULATED RADAR

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

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,

fd = Doppler frequency shift

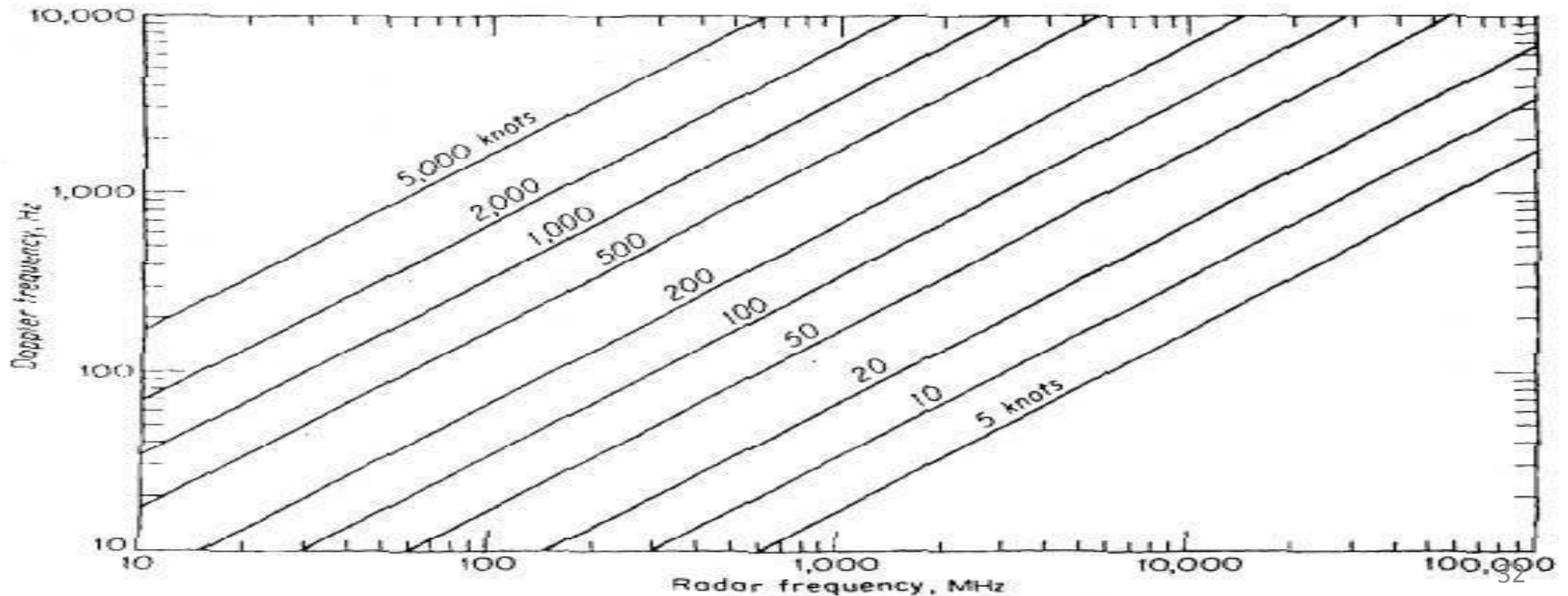
v_r = relative (or radial) velocity of target with to radar. The Doppler frequency shift is $fd = 2 * v_r / \lambda = 2 * v_r * f_0 / c$ where,

f_0 = transmitted frequency

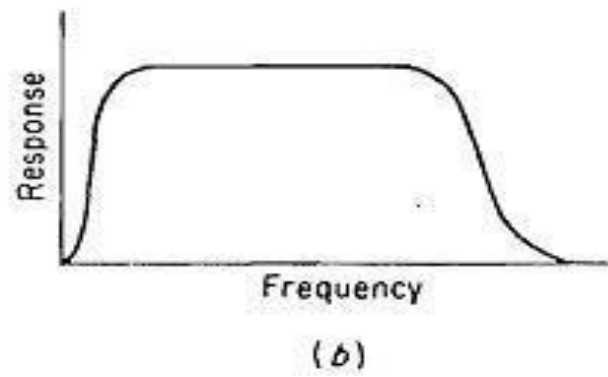
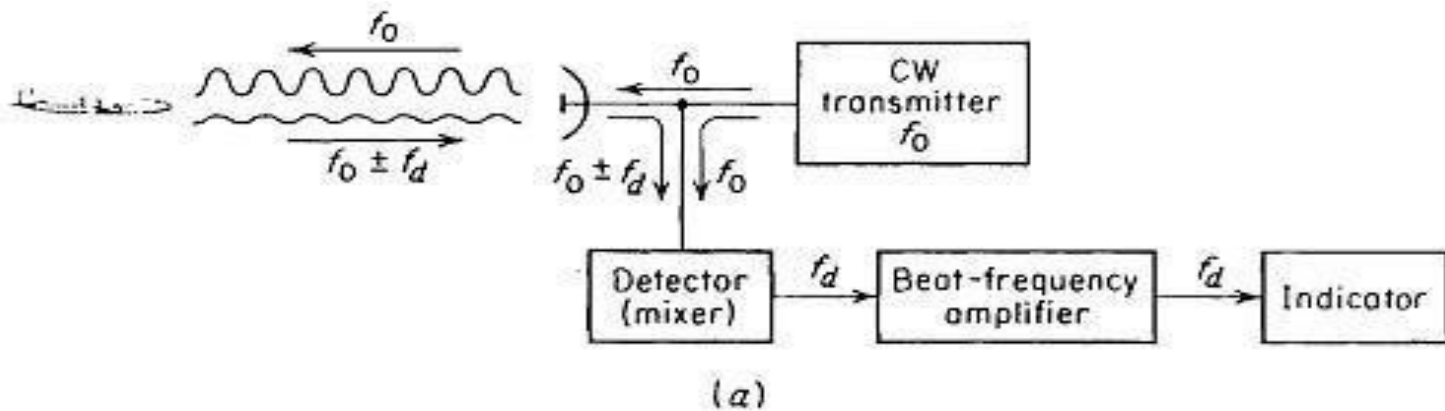
c = velocity of propagation = 3×10^8 m/s. If fd is in hertz v_r in knots, and λ in meters, $fd = 1.03 * v_r / \lambda$

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 $\theta = 0$. The Doppler frequency is maximum.
- The Doppler is zero when the trajectory is perpendicular to the radar line of sight ($\theta = 90^\circ$)



CW Radar Block Diagram



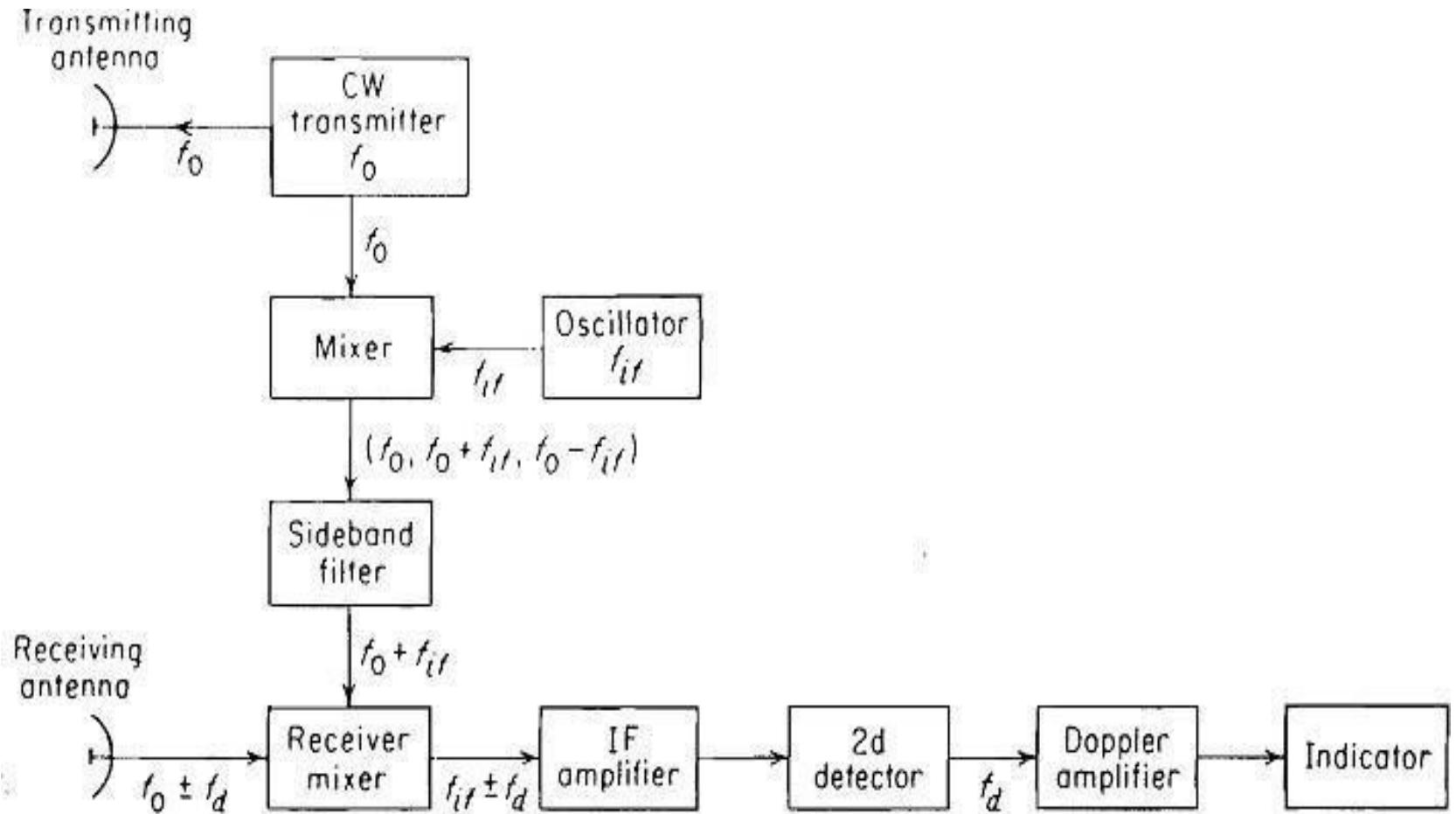
Isolation Between Transmitter and Receiver

- 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.

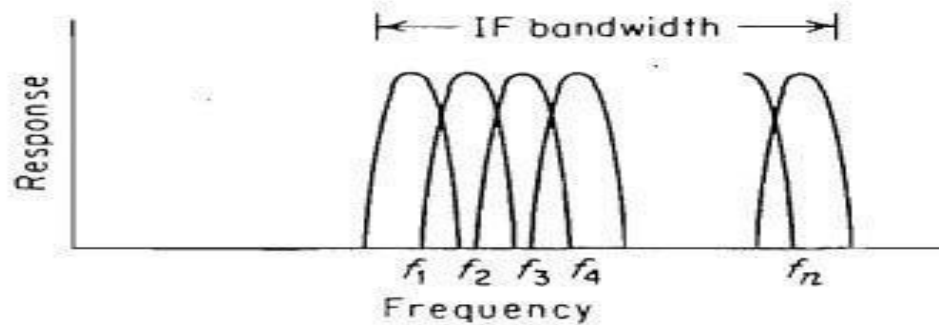
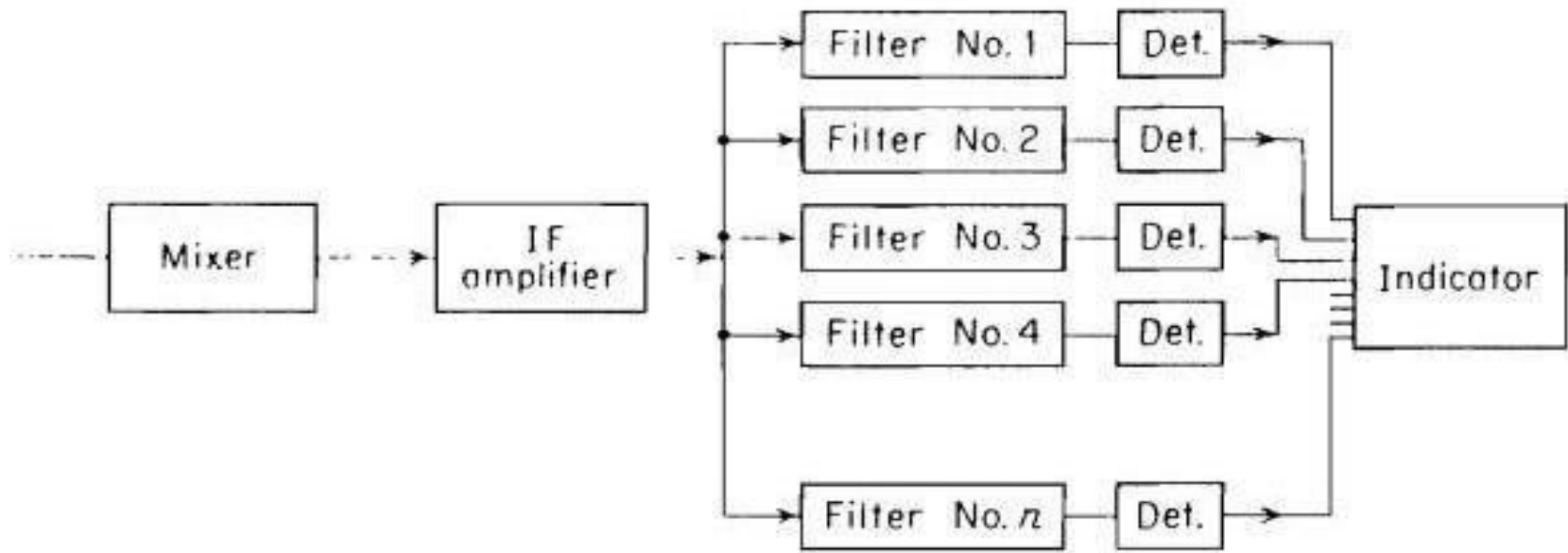
Isolation Between Transmitter and Receiver

- 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

Non Zero IF Receiver

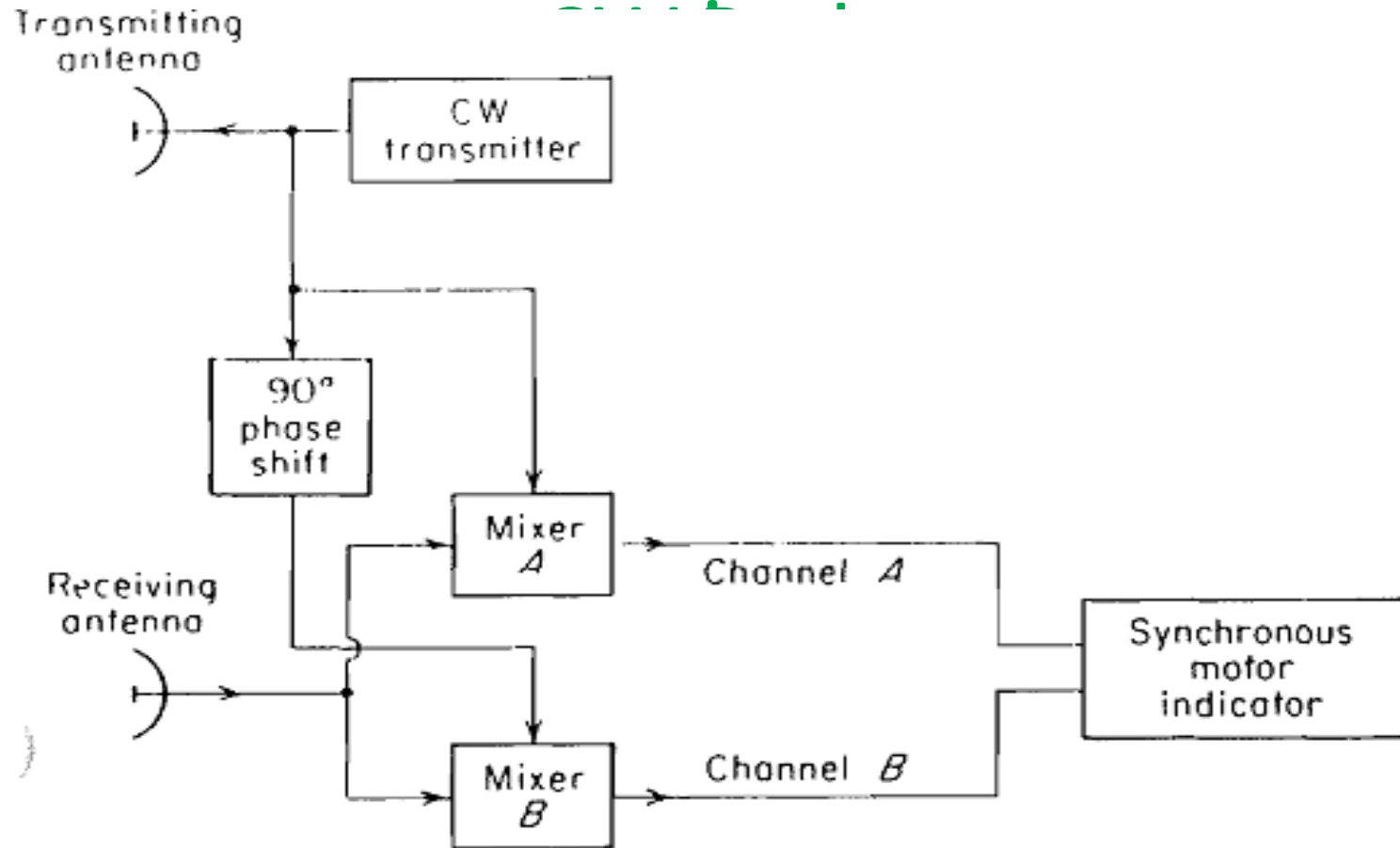


Receiver Bandwidth Requirements



(b)

Identification of Doppler Direction



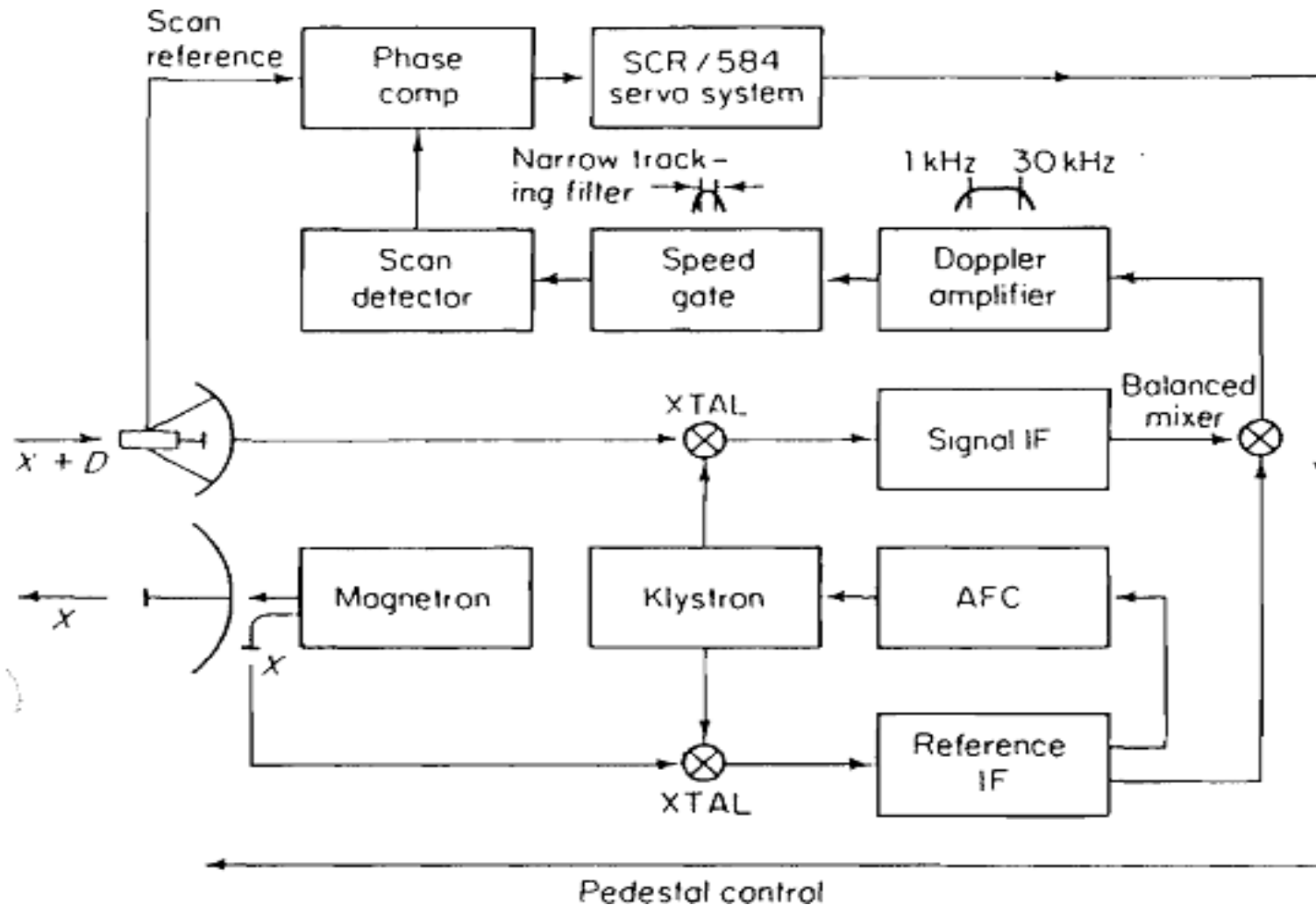
Identification of Doppler Direction in CW Radar

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

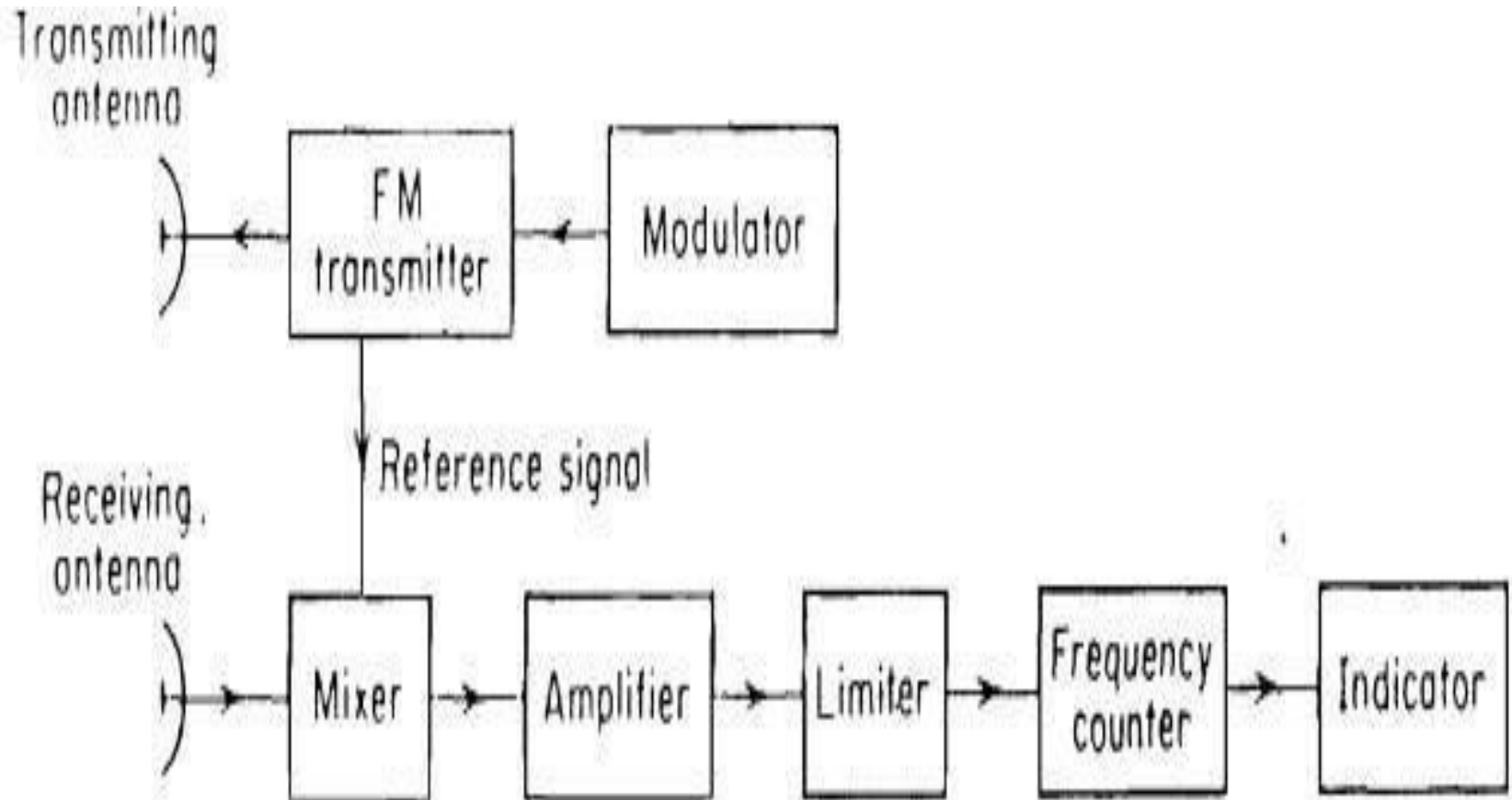
CW Radar Tracking Illuminator



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



Range and Doppler Measurement

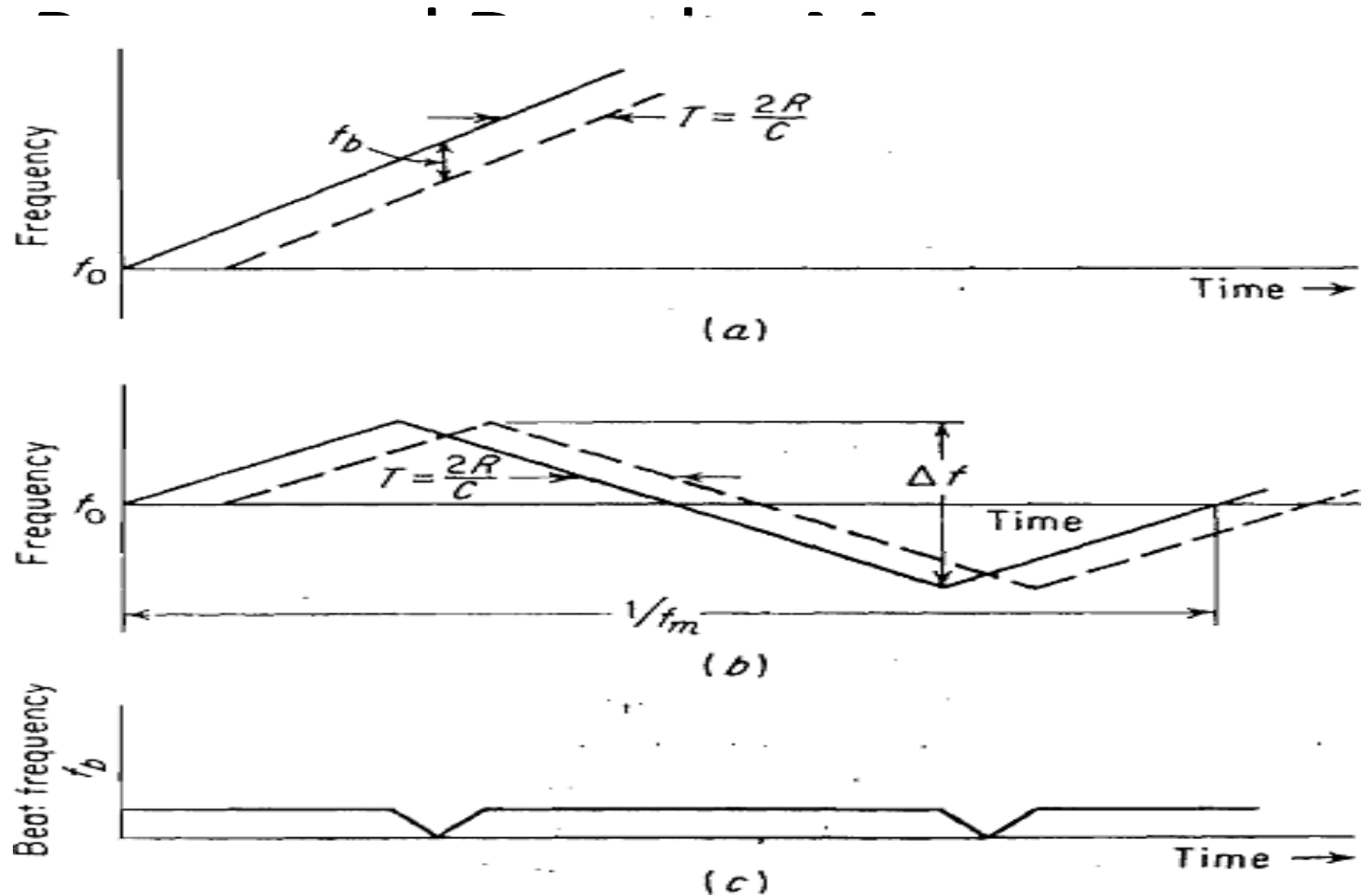
- If the rate of change of the carrier frequency is f_0 , the beat frequency is $f_r = f_0 T = 2 R f_0 / c$
- If the frequency is modulated at a rate f_m over a range

Δf , the beat frequency is

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

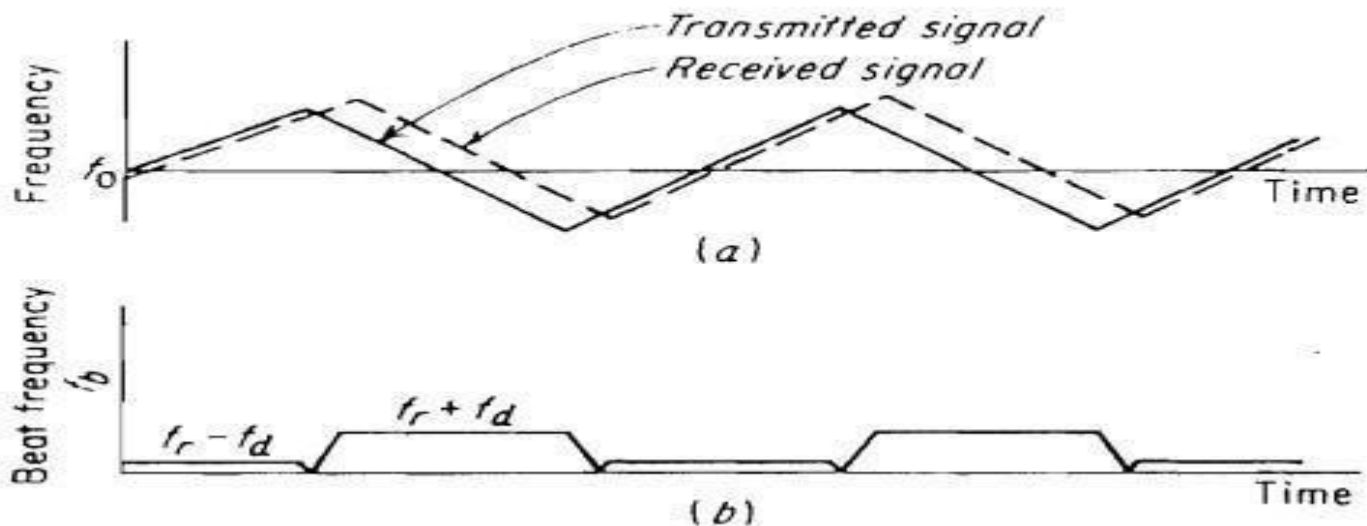
- Measurement of the beat frequency determines the range R.

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



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

Range and Doppler Measurement

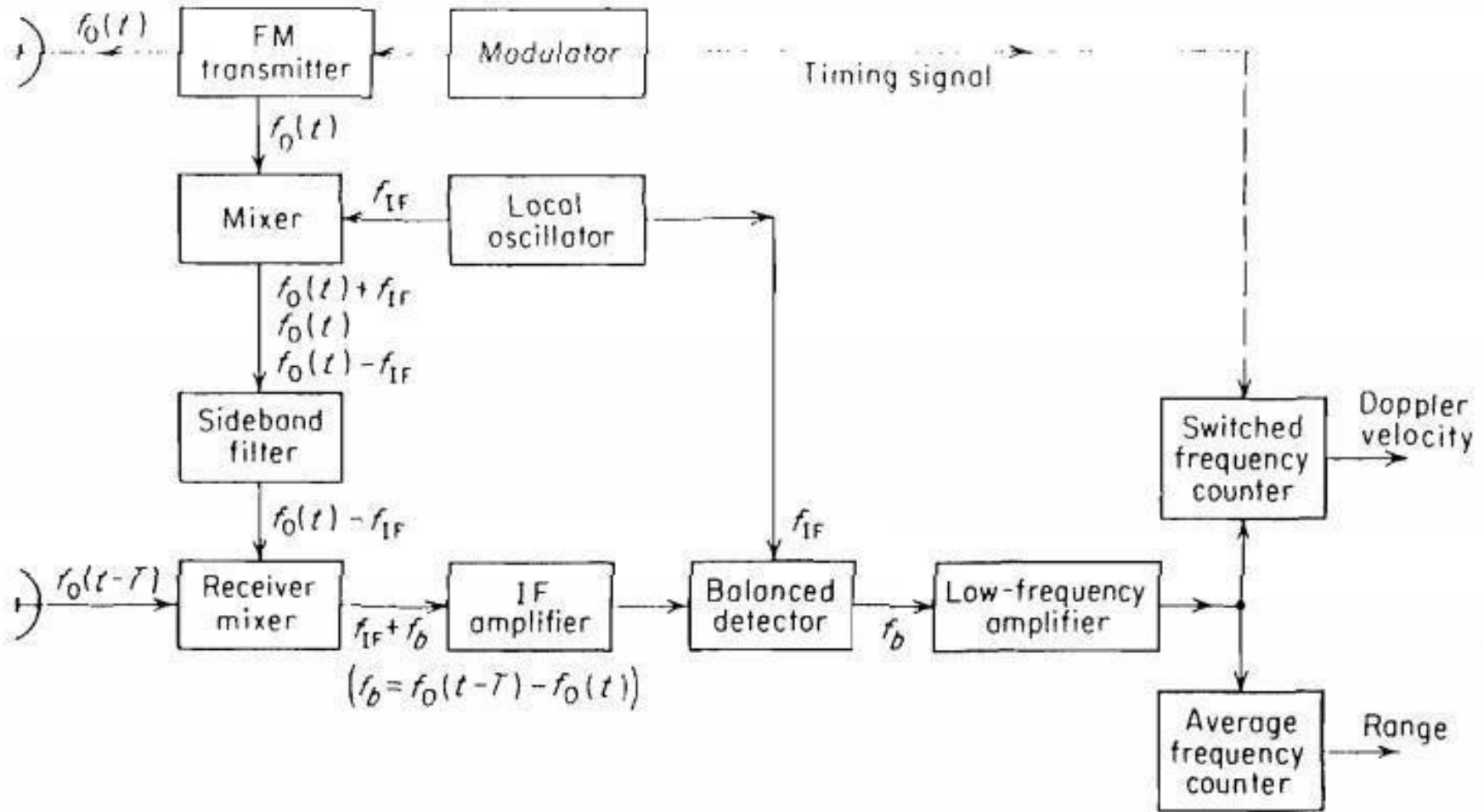


- (a) Transmitted (solid curve) and echo (dashed curve)
- (b) beat frequency

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
- $f_r < f_d$ Approaching
 Target Receding

FMCW Altimeter



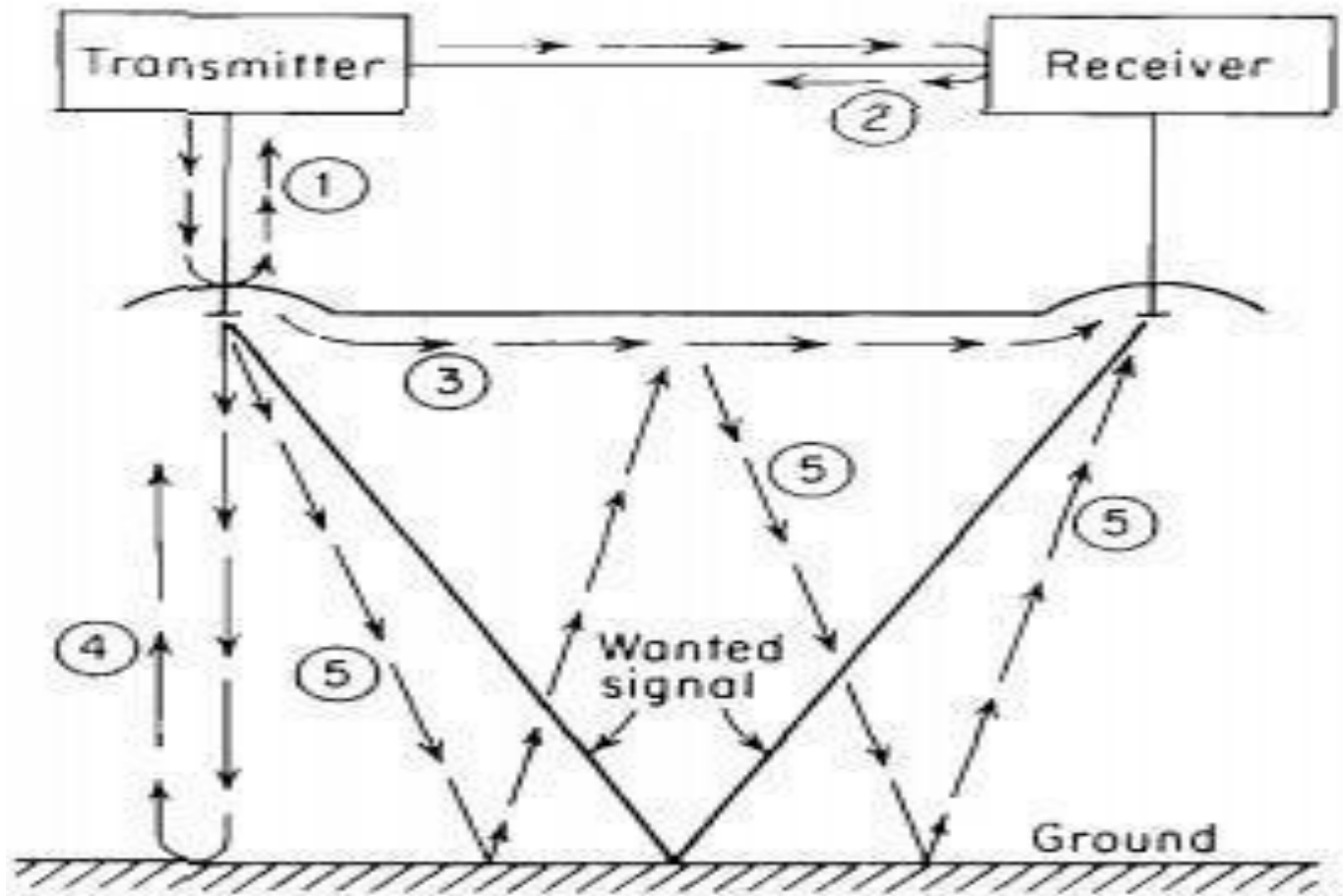
Measurement Errors

- 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 f_b 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

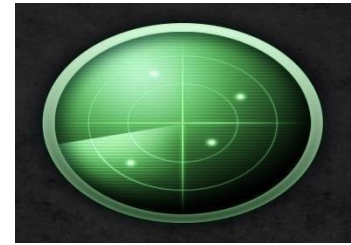
Measurement Errors

- $R = c N / 4 \Delta f$
- 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
$$\delta R = c / 4 \Delta f$$
$$\delta R \text{ (m)} = 75 / \Delta f \text{ (MHz)}$$

Unwanted Signals

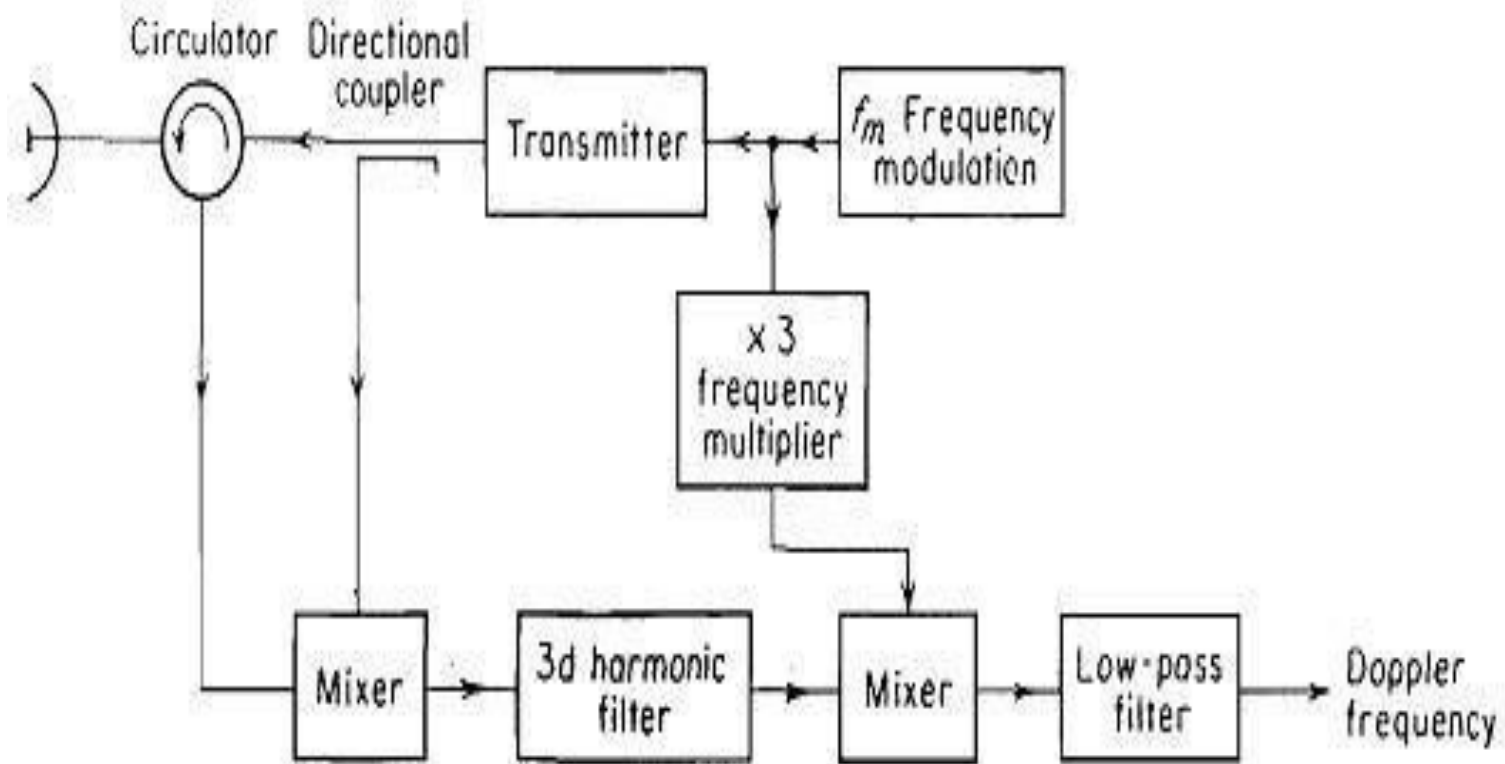


Unwanted Signals



- 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.

Sinusoidal Modulation (3rd Harmonic) Extraction



Multiple Frequency CW Radar

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

$$v_{1r} = \sin(2\pi f_1 t + \phi_1) \quad v_{2r} = \sin(2\pi f_2 t + \phi_2)$$

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

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

a) Doppler effect The form of the doppler shifted

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

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

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

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

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

Multiple Frequency CW Radar

- The phase difference between these two components is

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

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

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.

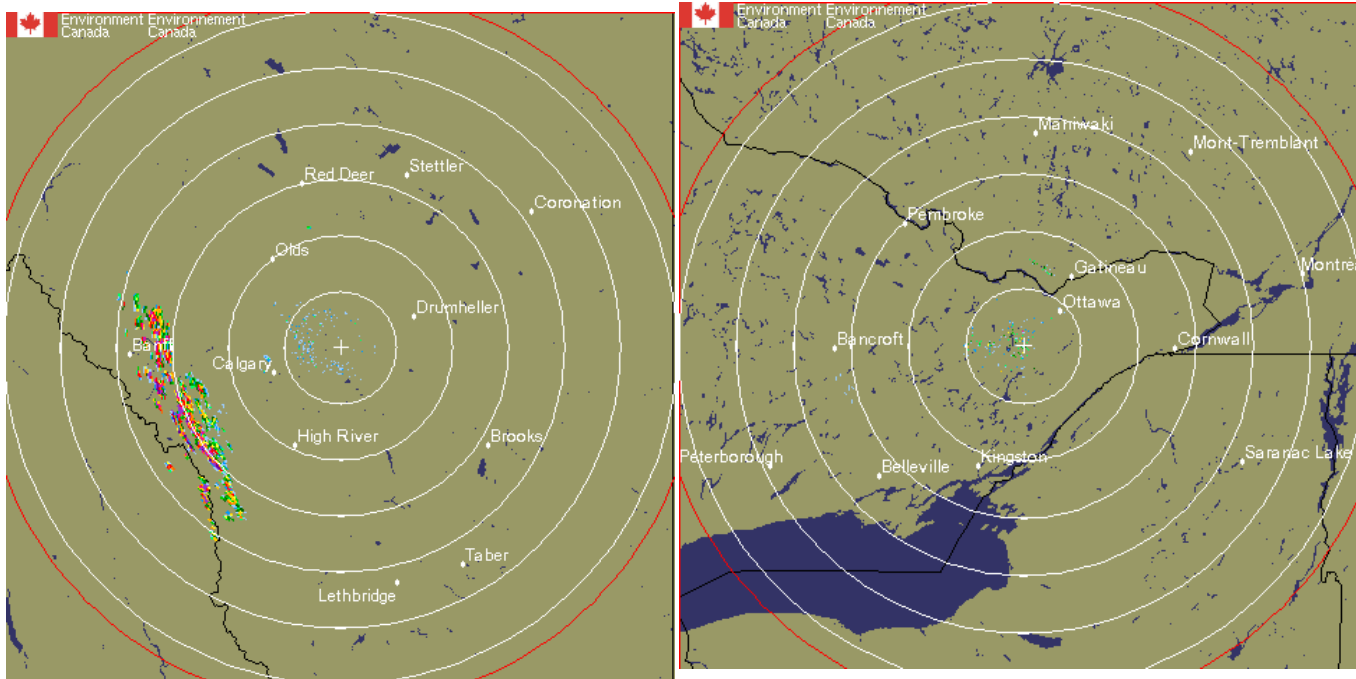
Unit III

MOVING TARGET INDICATION AND PULSE DOPPLER RADAR

Moving Target Indicator Radar (MTI)

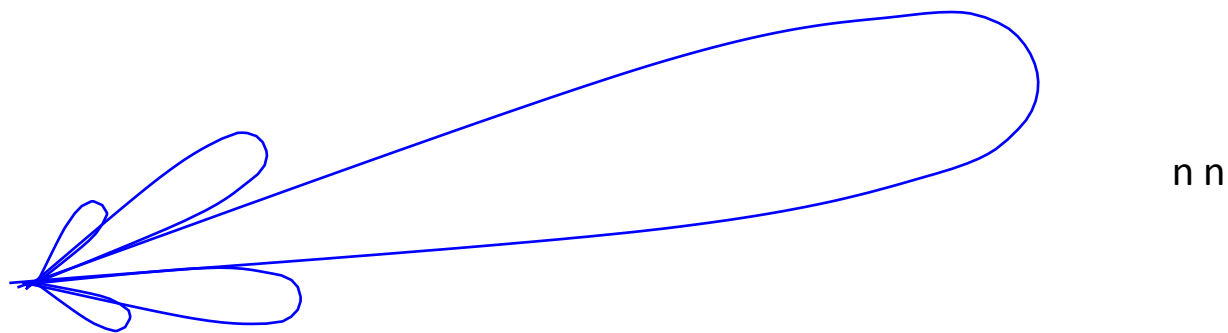
Clutter is the term used for radar targets which are not of interest to the user.

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



Moving Target Indicator Radar (MTI)

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



In any case it is desirable to eliminate as much clutter as possible

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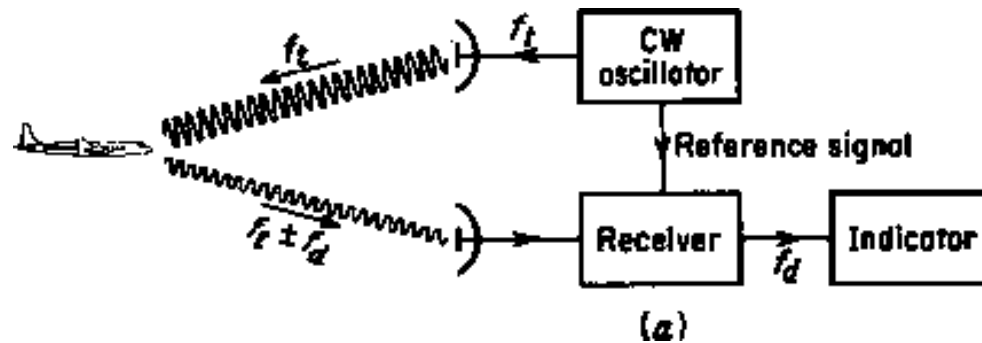
Moving Target Indicator Radar (MTI)

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.

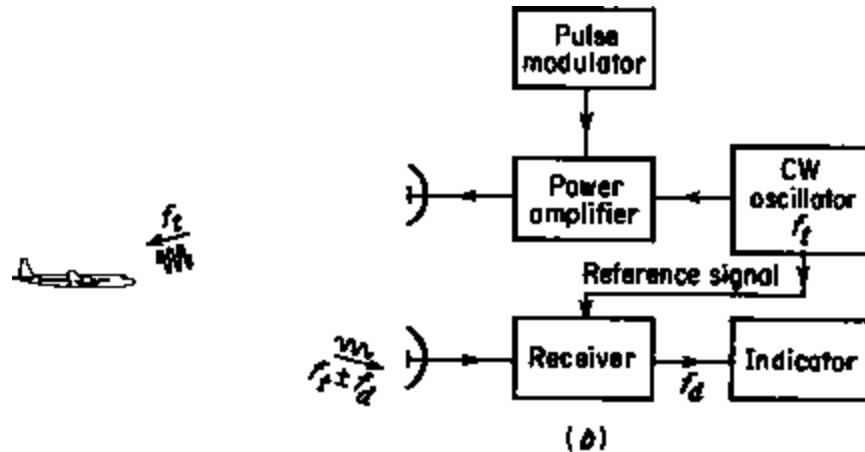
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Moving Target Indicator Radar (MTI)

The simple CW example can be modified to incorporate pulse modulation



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

Thus the return is processed **coherently**

i.e. the phase of the signal is preserved

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

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

n

n

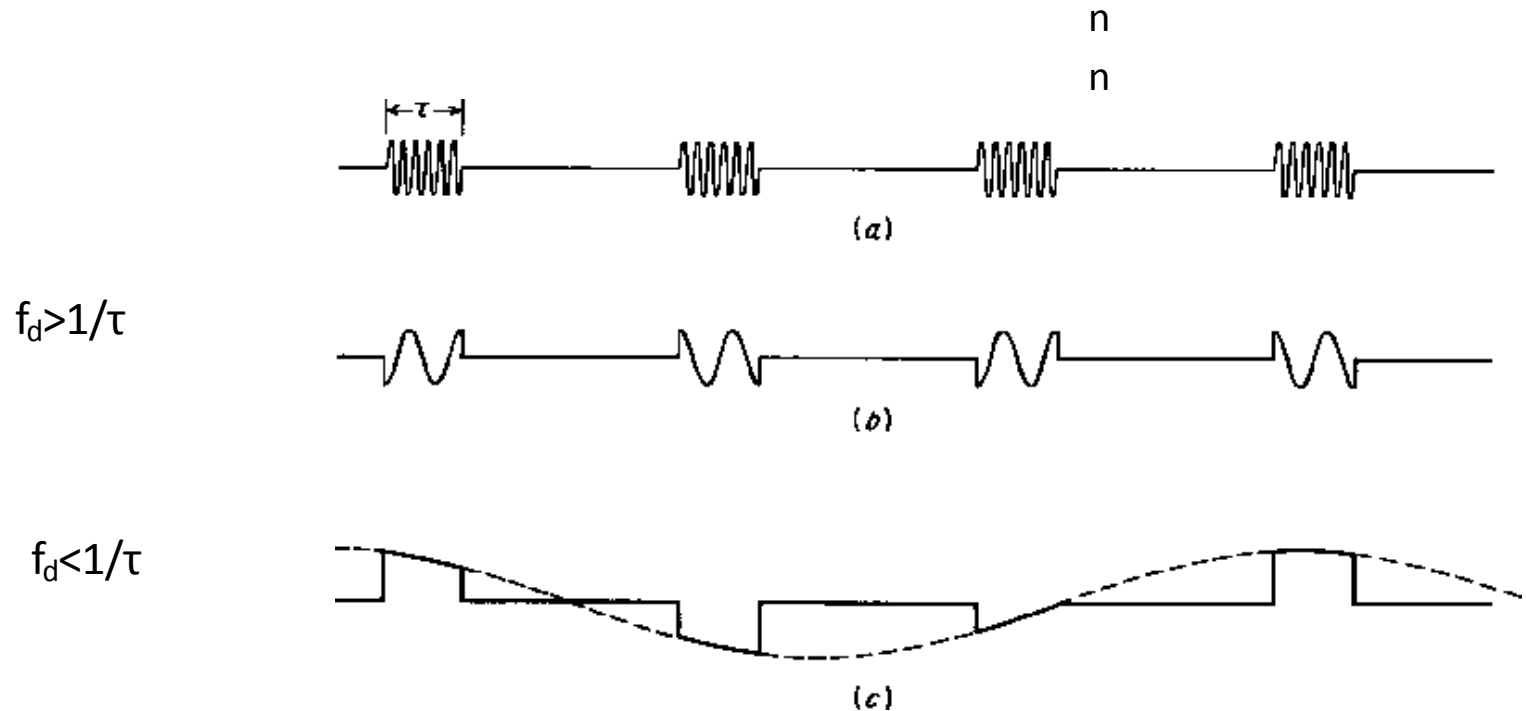
This has two components, one is a sine wave at Doppler frequency, the other is a phase shift which depends on the range to the target, R_0

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



Moving Target Indicator Radar (MTI)

Note that for a pulse width of $1\mu\text{s}$, 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

n
n

e.g. Nyquist's criterion

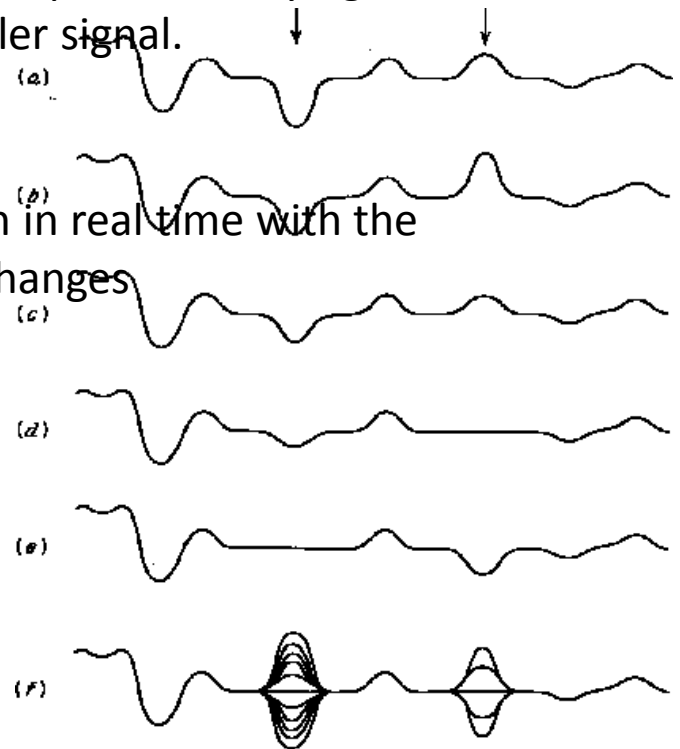
We shall also see that we can use Discrete Sample Processing (DSP) to handle some of the problems

n
n

Moving Target Indicator Radar (MTI)

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

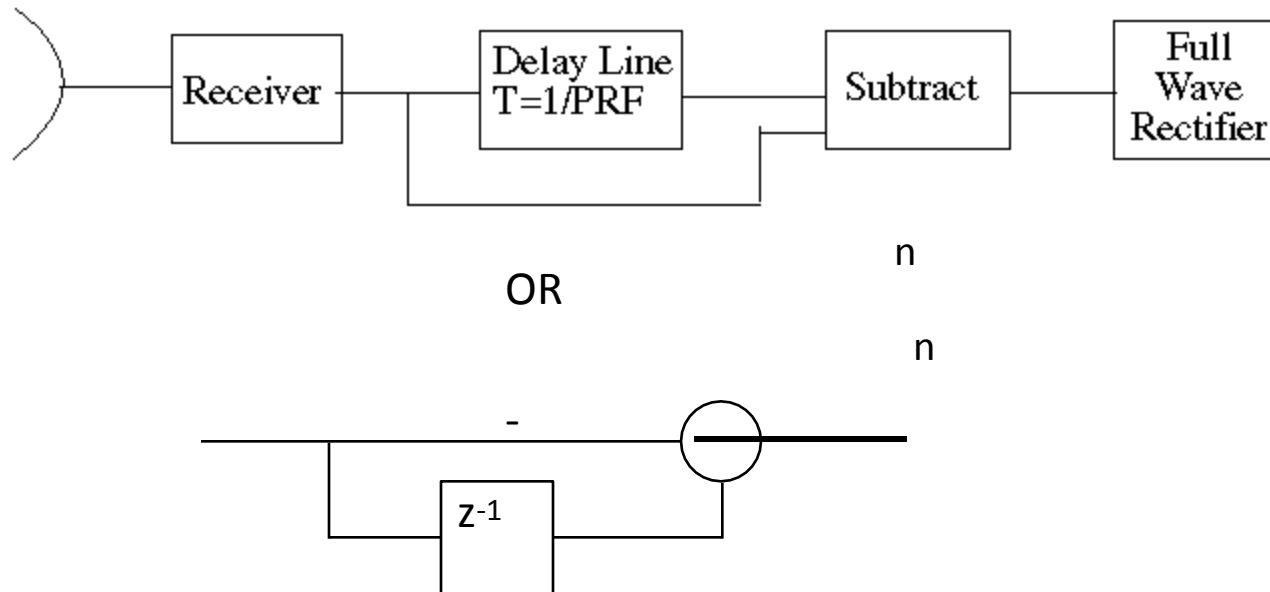
At the ranges of the two targets, the return amplitude is varying as the radar samples the (relatively) slow Doppler signal.



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

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:



Moving Target Indicator Radar (MTI)

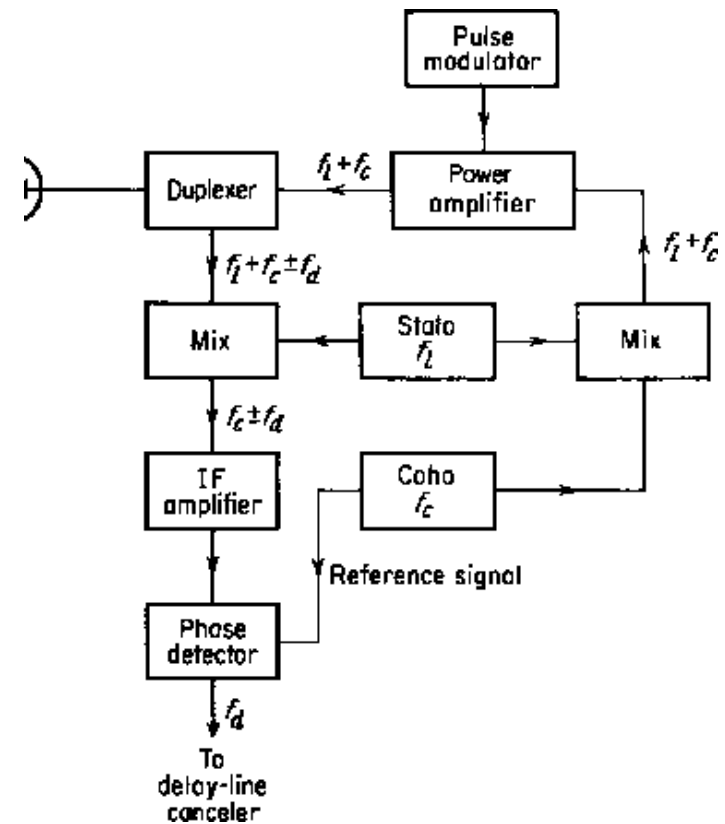
MTI Radar Block Diagrams

MOPA (master oscillator, power amplifier)

Power amplifiers: Klystron

TWT (Travelling wave tube) Solid State

(Parallel)



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.

n

n

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

n

n

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

Moving Target Indicator Radar (MTI)

The Filtering Characteristics of a Delay Line Canceller

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

$$v_n = \frac{n\lambda f_p}{2}$$

where n
is
0,1,2,3,...

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

n

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

n

n

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:

- a. operating with multiple prfs n
- b. operating with multiple carrier frequencies n

n

n

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

Moving Target Indicator Radar (MTI)

Double Cancellation:

There are two implementations:

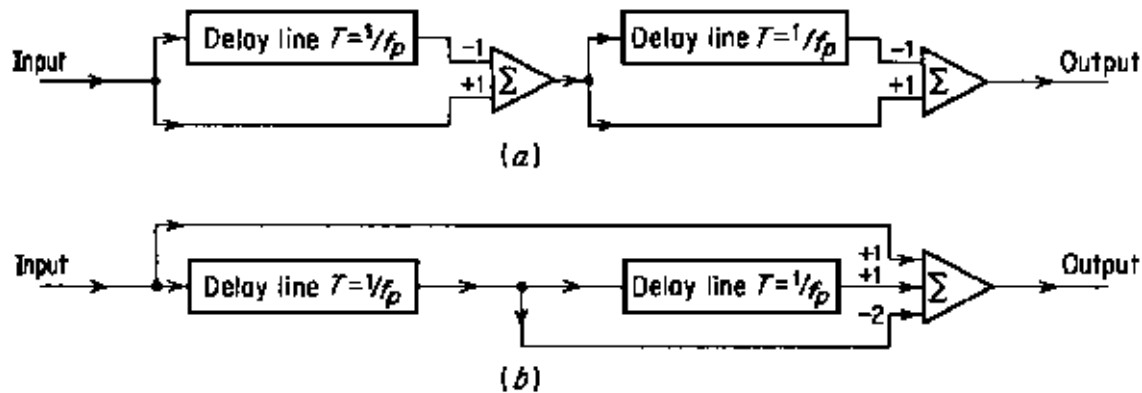


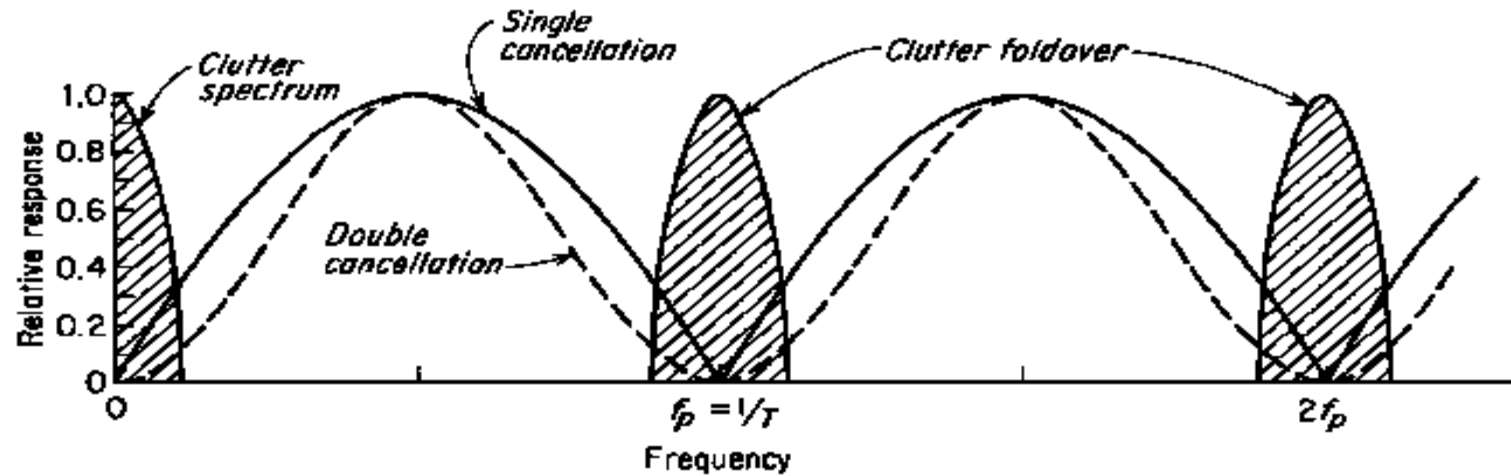
Figure 4.9 (a) Double-delay-line canceler; (b) three-pulse canceler.

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

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

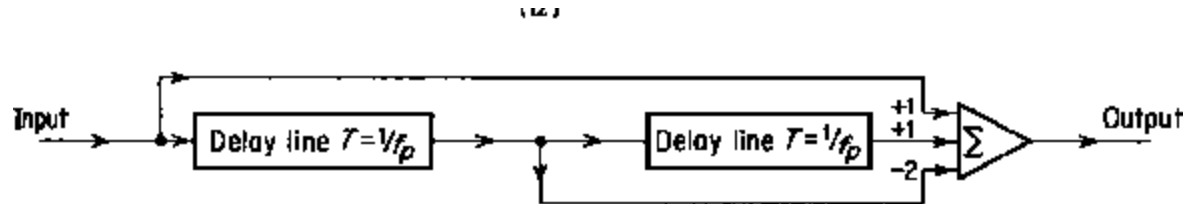
Moving Target Indicator Radar (MTI)

Double Cancellation:

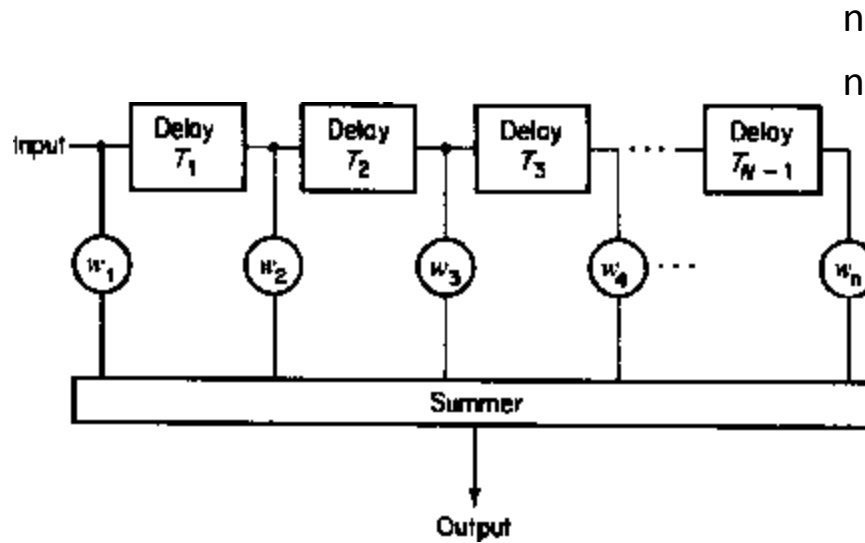


Moving Target Indicator Radar (MTI)

Transversal Filters



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



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.

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

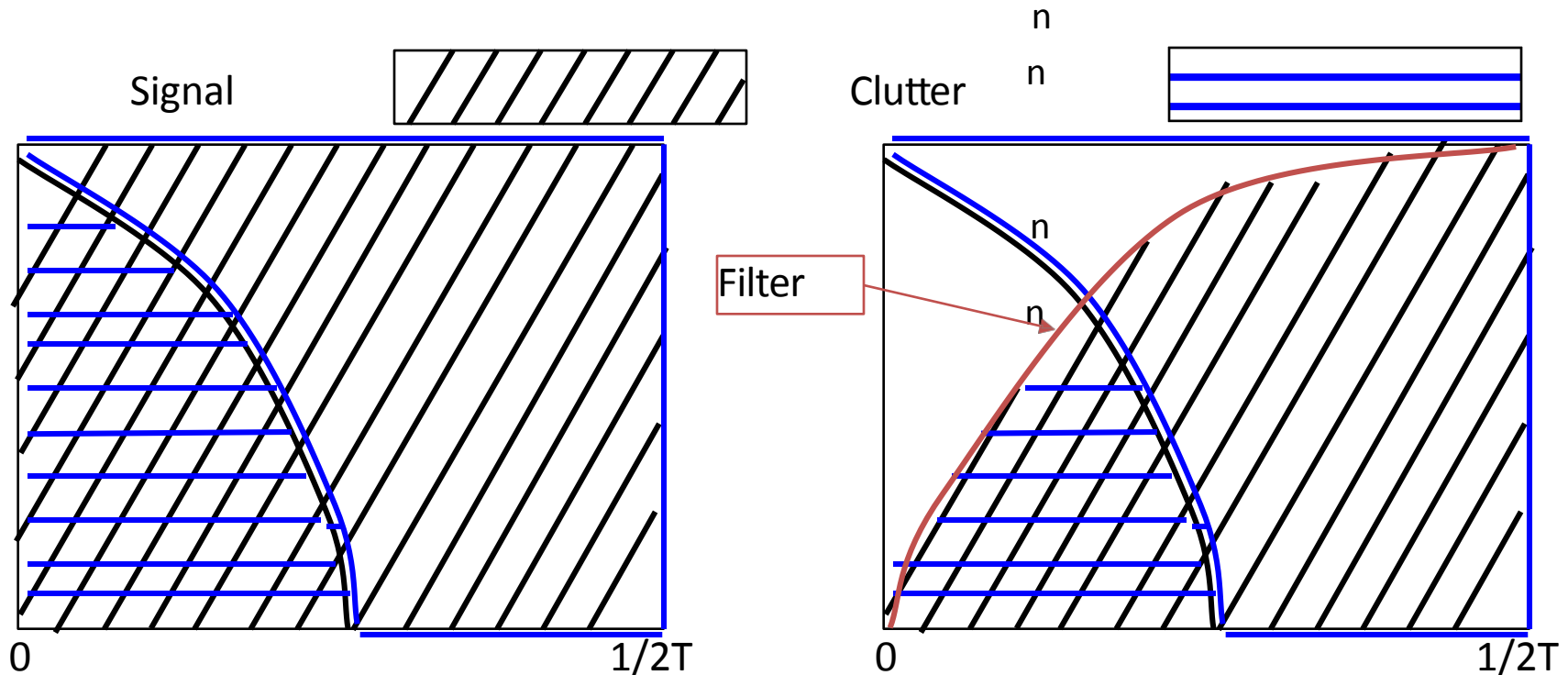
Moving Target Indicator Radar (MTI)

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 n

It is normalized, (or adjusted) to the signal attenuation of the canceler.

i.e. the inherent signal attenuation of the canceler n is ignored

n

Moving Target Indicator Radar (MTI)

Transversal Filters with Binomial Weighting with alternating sign

Advantages:

Close to optimum for maximizing the Clutter improvement factor

C_{in}/C_{out}

Also close to maximizing the Clutter Attenuation I_C

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

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 _{n} of legitimate targets.

n

n

n

% 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.

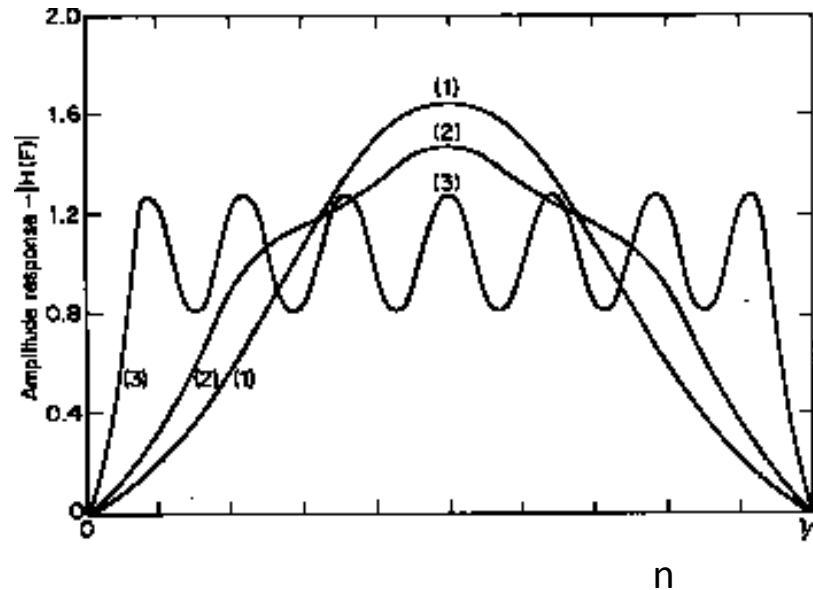
Unfortunately the number of pulses is limited by the scan rate and the

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

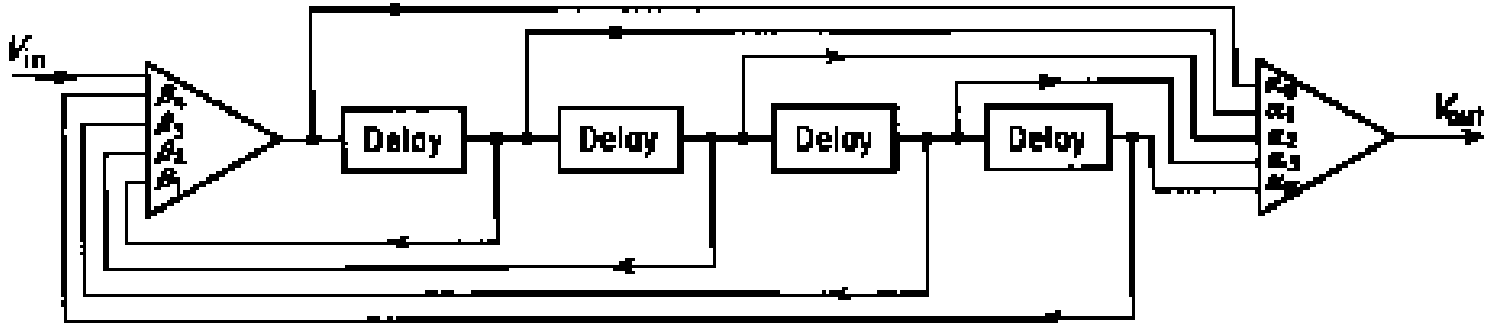
(3) 15 pulse Chebyshev filter

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

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.

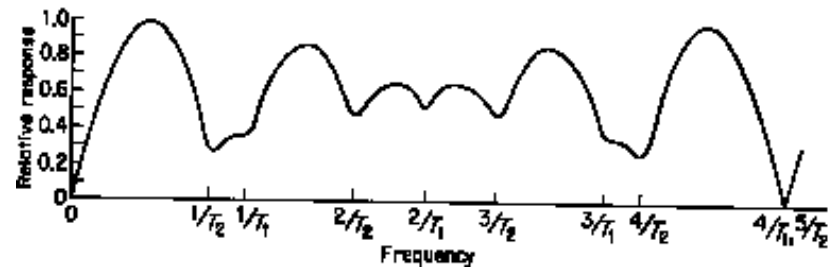
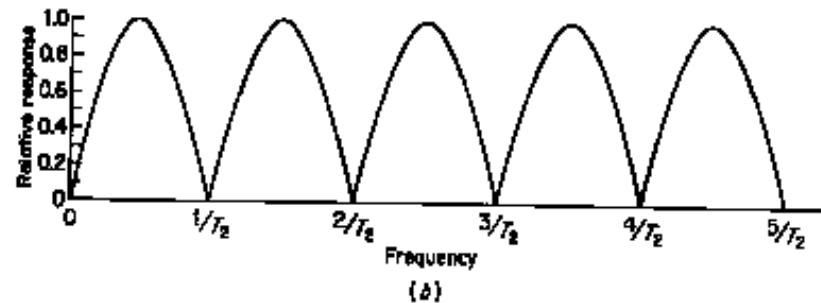
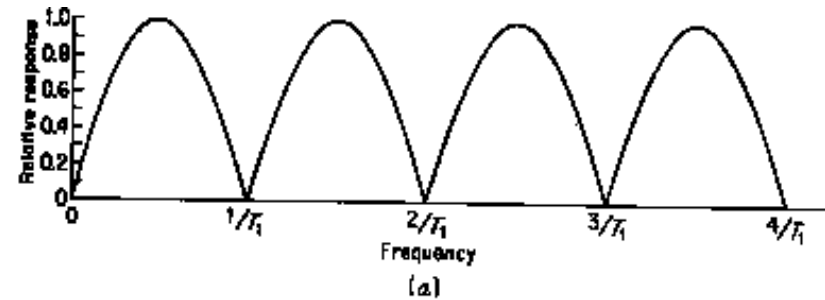
Moving Target Indicator Radar (MTI)

Multiple PRFs: Example

Two PRFs Ratio 4/5

First blind speed is at

$5/T_1$ or $4/T_2$



Moving Target Indicator Radar (MTI)

Multiple PRFs: Example

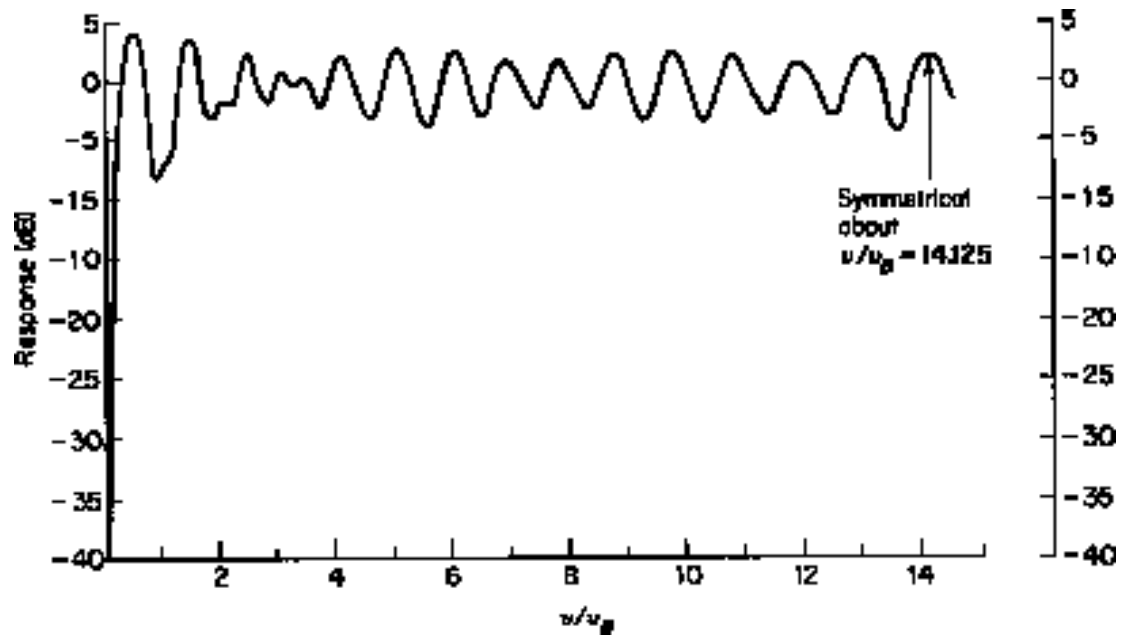
Four PRFs

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



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

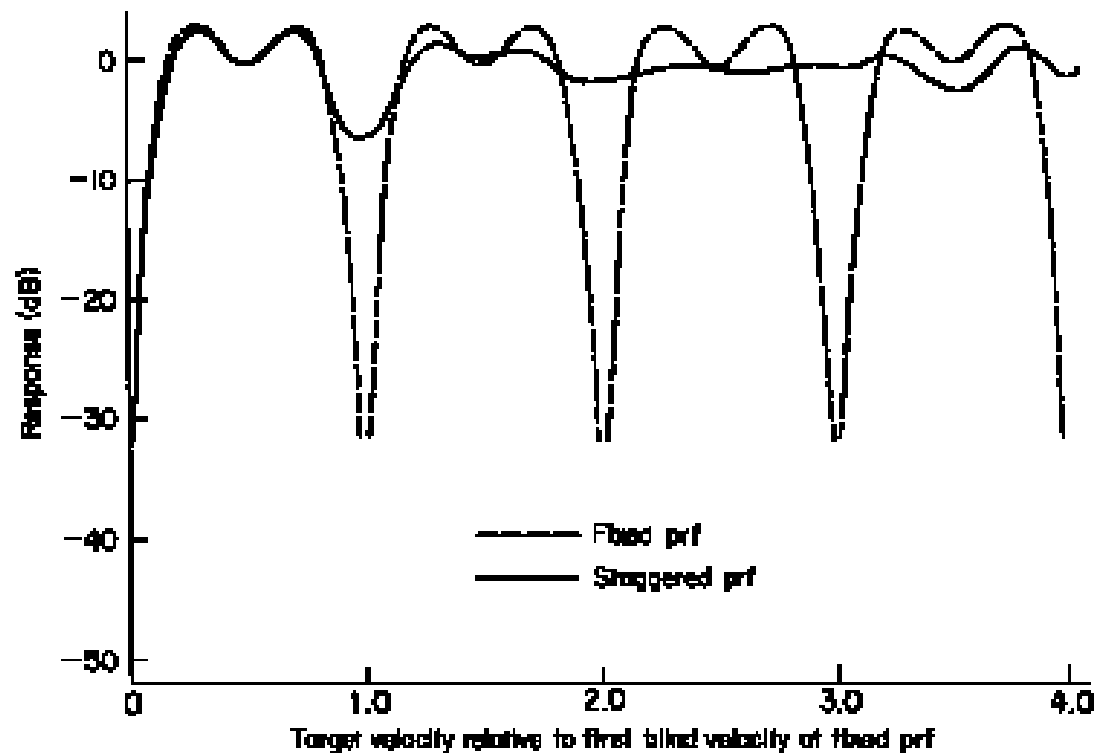
$$v_1 = v_B \left[\frac{n_1 + n_2 + \dots + n_N}{N} \right]$$

Moving Target Indicator Radar (MTI)

Multiple PRFs can also be used with transversal filters

Example

5 pulse canceler with 4 staggered PRFs

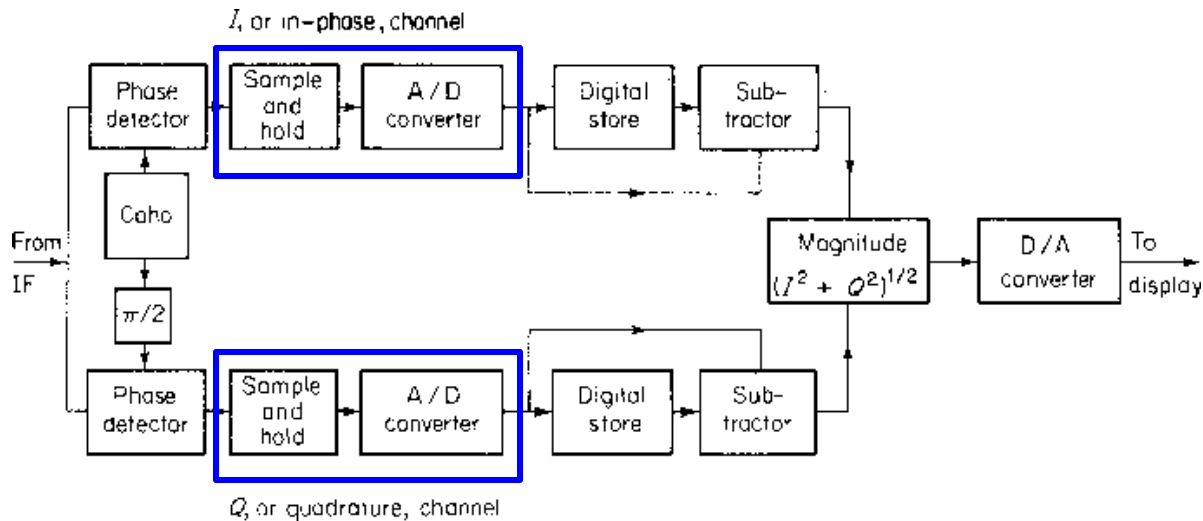


Moving Target Indicator Radar (MTI)

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

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

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.

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

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

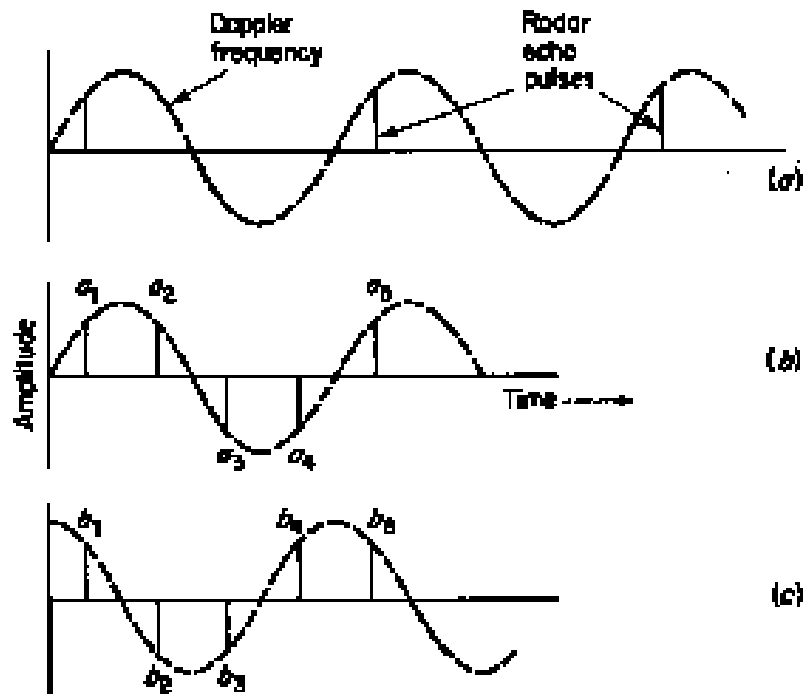
Note: A 10 bit A/D gives a dynamic range of 45.2dB

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

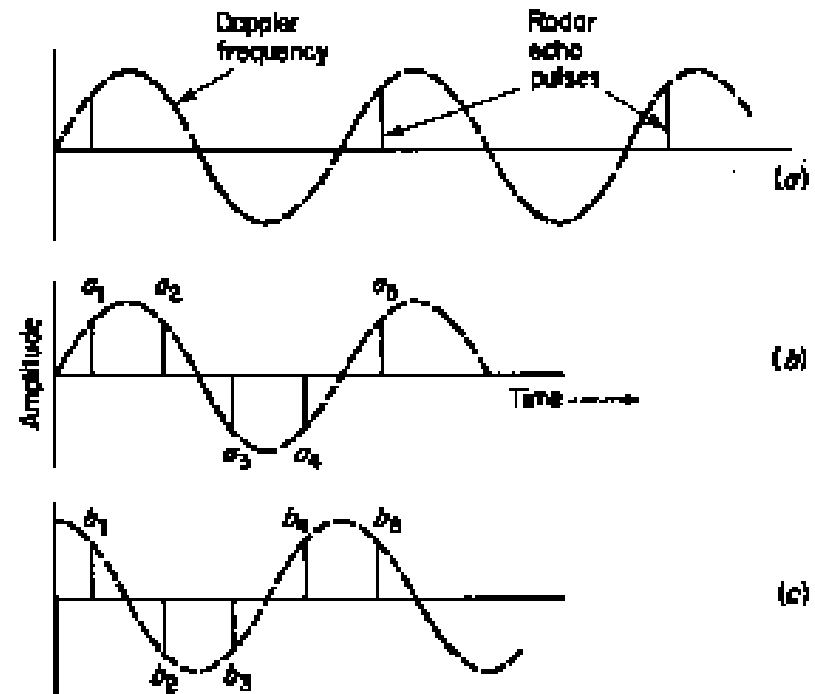


Moving Target Indicator Radar (MTI)

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)

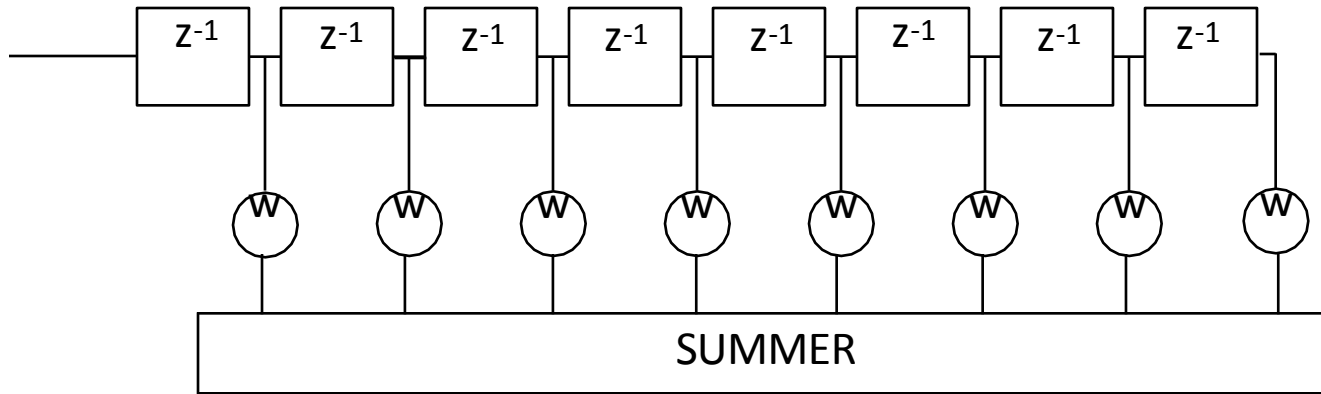
By using both inphase and quadrature signals, blind phases can be eliminated



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 $N-1$

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

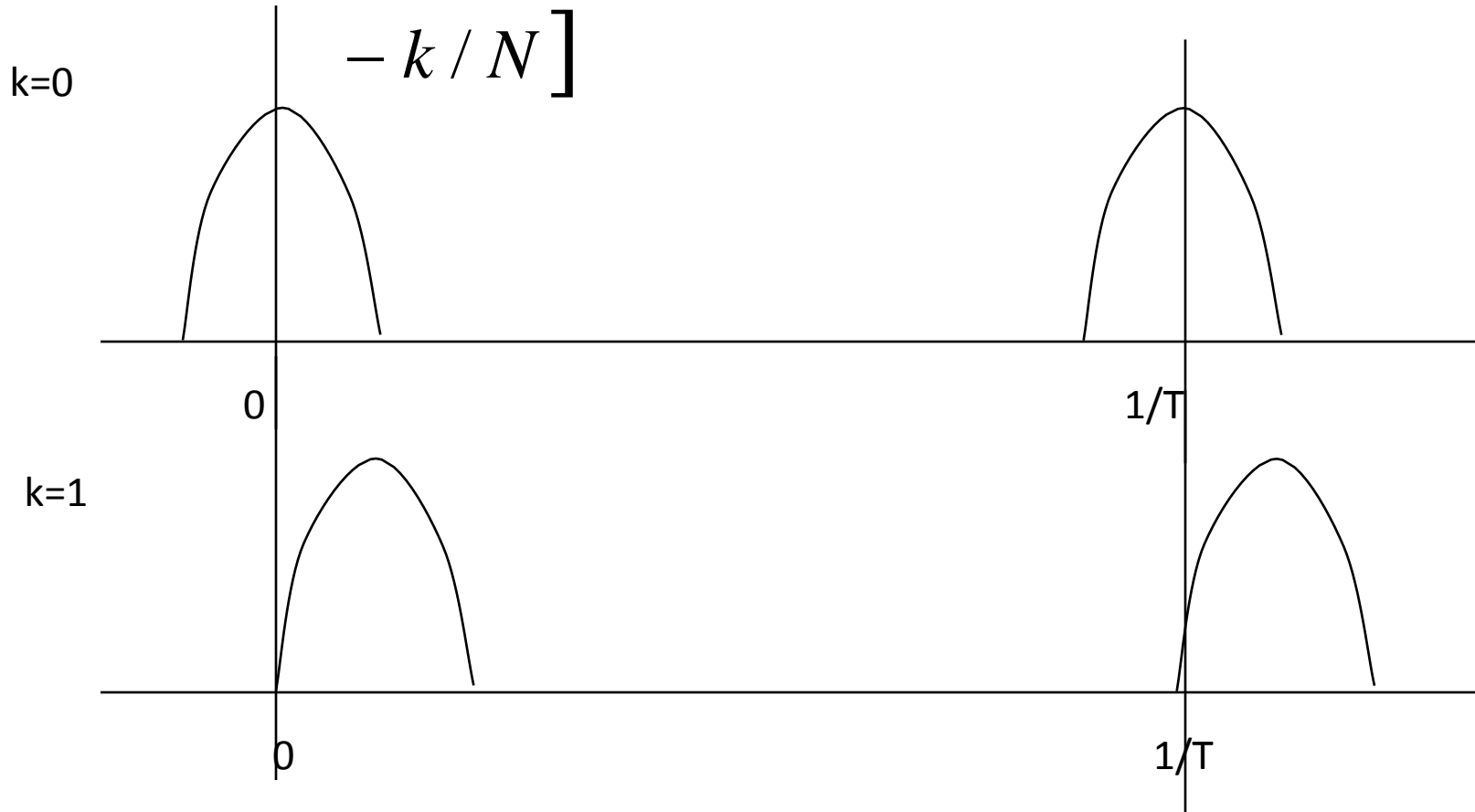
$$H_k(f) = e^{-j2\pi fT} \sum_{i=1}^N e^{j2\pi(i-1)[fT - k/N]}$$

The magnitude of the response is

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

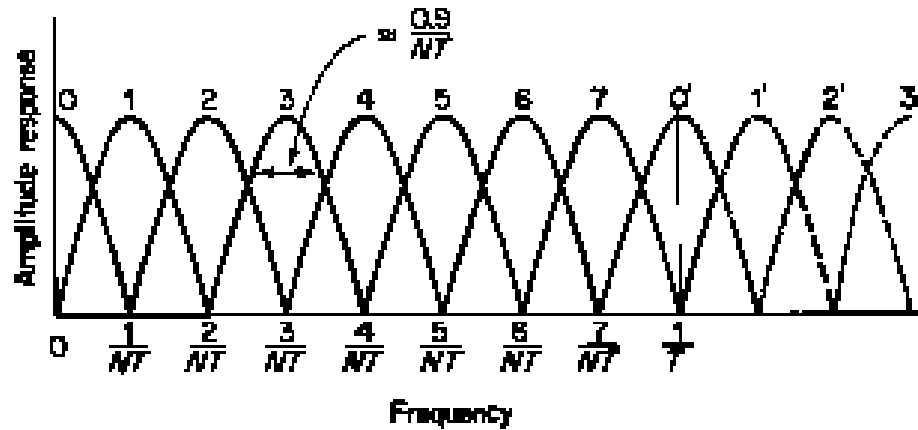
Moving Target Indicator Radar (MTI)

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



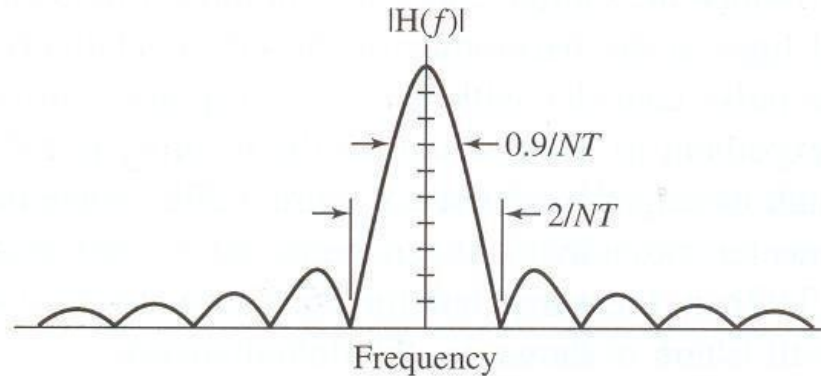
Moving Target Indicator Radar (MTI)

The response for all eight filters is:



Moving Target Indicator Radar (MTI)

The actual response for this filter is:



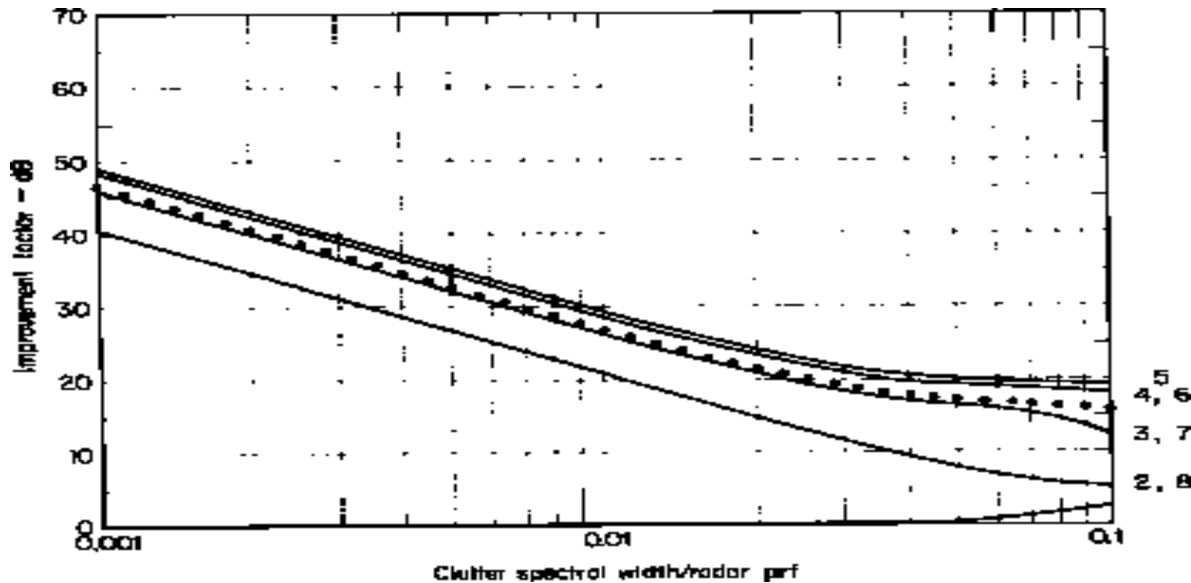
Which is $\sin(Nx)/\sin(x)$

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

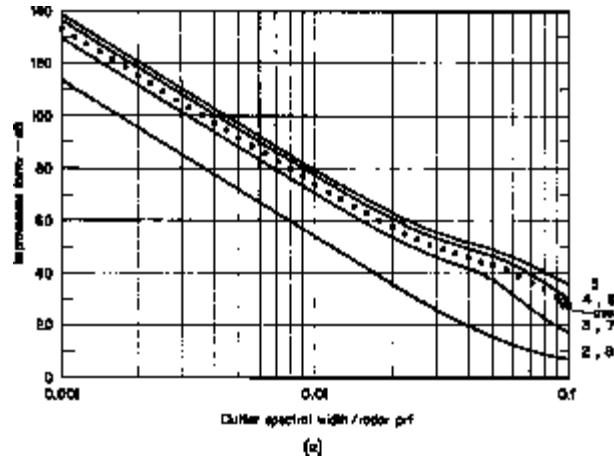


Clutter Improvement with Uniform weighting (Filter Bank Only)

Moving Target Indicator Radar (MTI)

Filter Banks can also be preceded by cancelers

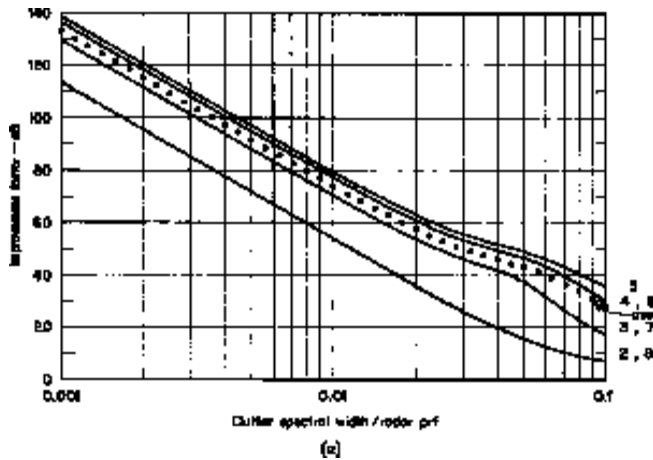
In the following cases a 3 pulse canceler



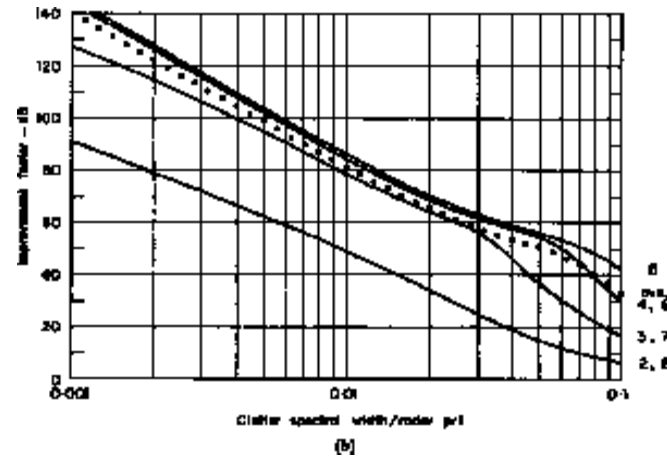
Moving Target Indicator Radar (MTI)

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

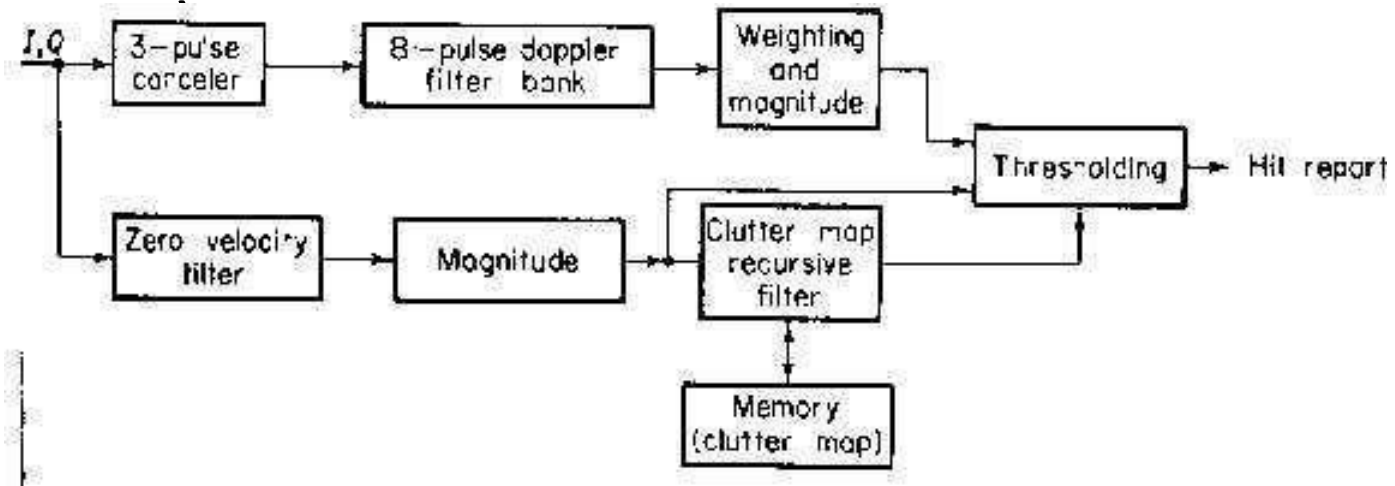


Chebyshev

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

Example: ASR

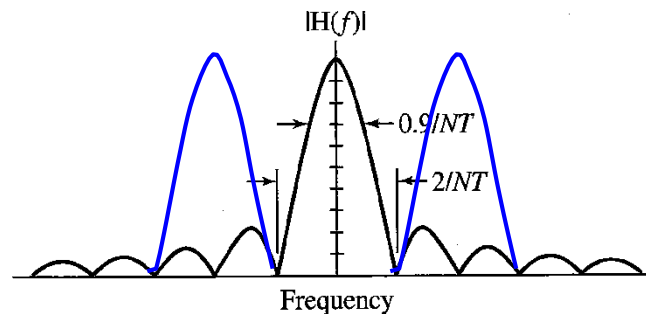
(Airport`Surveillance Radar



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

Example: ASR (Airport Surveillance Radar)

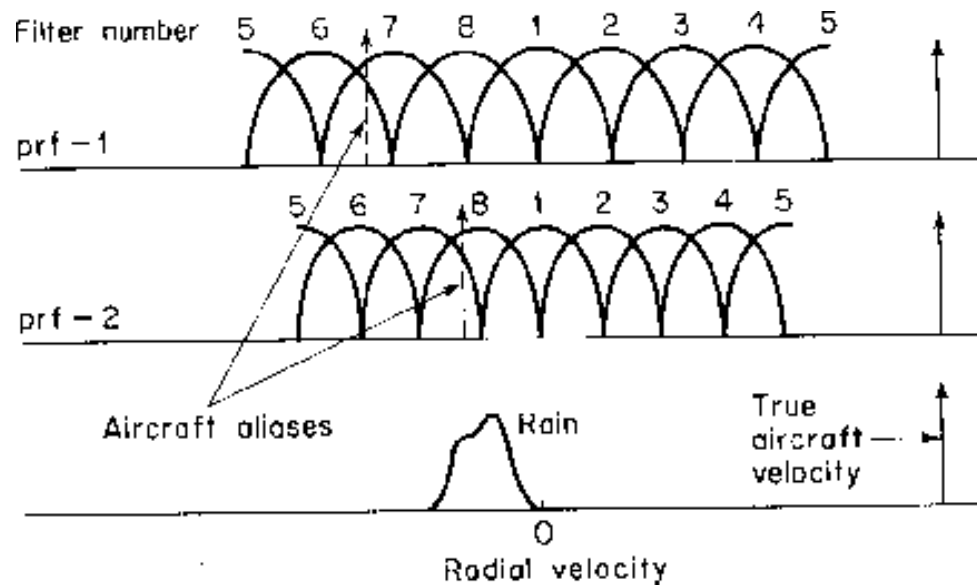
After the filter bank the doppler filter outputs are weighted to reduce the effects of the sidelobes in the filter



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

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

Example: ASR (Airport Surveillance Radar)



Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Definitions:

- MTI Improvement Factor (I_f)

- Defined earlier

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

- Subclutter Visibility(SCV)

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

$$SCV = (C/S)_{IN}$$

- The Signal to Clutter ratio

after filtering that provides the specified P_d and P_{fa}.

$$V_{OC} = (S/C)_{OUT}$$

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

N

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

Moving Target Indicator Radar (MTI) Limitations of MTI

Equipment Instabilities:

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

n

Moving Target Indicator Radar (MTI) Limitations of MTI

Equipment Instabilities:

Example: Phase variation Performance

g_1 and g_2 are successive pulses
for a stationary target

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

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

"
n

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 I

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

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Equipment Instabilities:

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

n

Note that if we need

$I_C=40\text{dB}$, n

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

n

Moving Target Indicator Radar (MTI) Limitations of MTI

Equipment Instabilities:

Some examples of the effects of instability on Performance

Transmitter frequency	$(\pi\Delta f\tau)^{-2}$	where	$\Delta f =$ interpulse frequency change
Stalo or coho frequency	$(2\pi\Delta fT)^{-2}$		$B =$ bandwidth
Transmitter phase shift	$(\Delta\phi)^{-2}$		$\tau =$ 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	$\tau^2/(\Delta\tau)^2 B\tau$		$\Delta t =$ timing jitter
Pulse amplitude	$(A/\Delta A)^2$		$\Delta\tau =$ pulse width jitter
			$\Delta A =$ interpulse amplitude change

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)

and

Sea: translational motion with variation in phase magnitude
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:

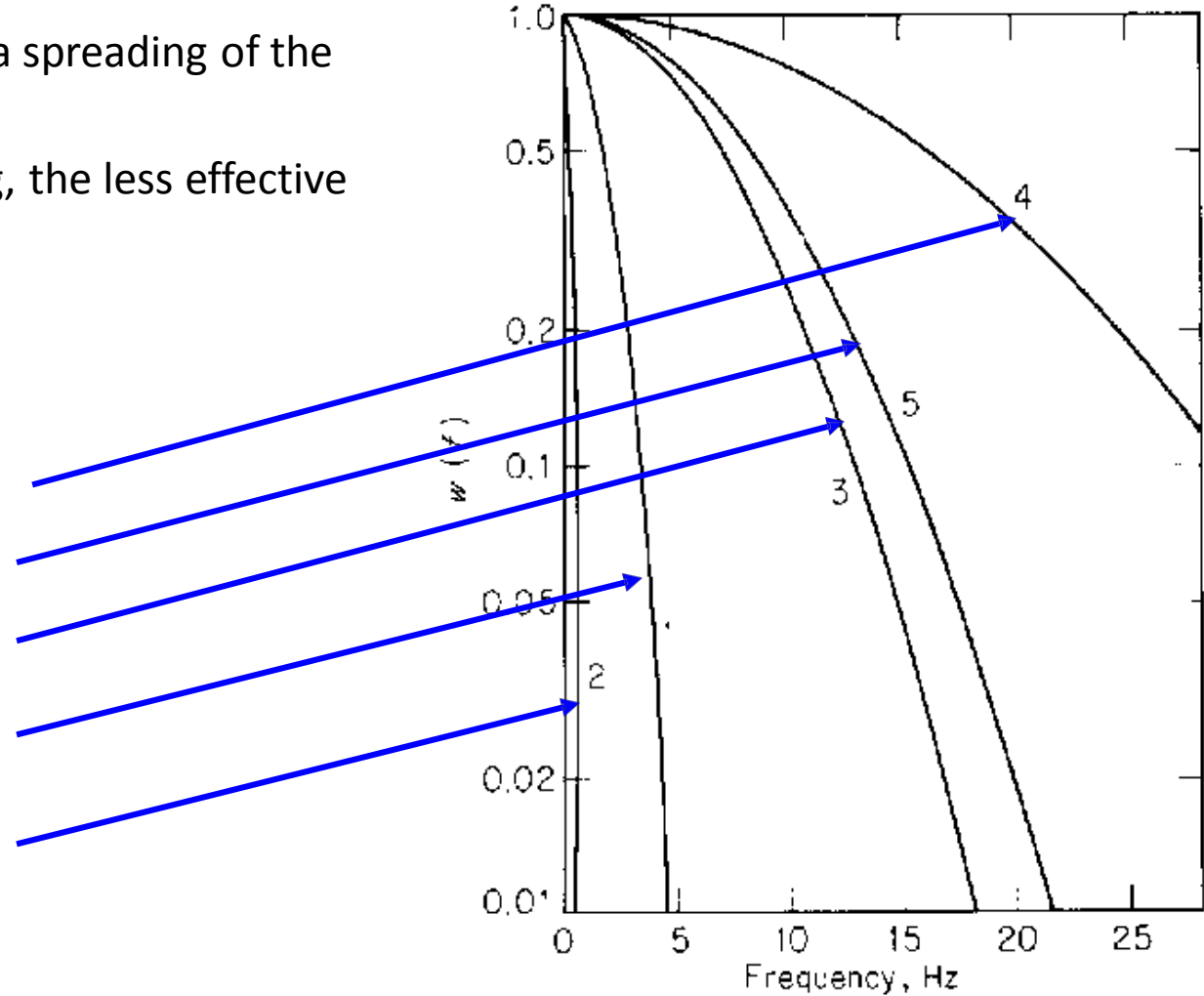
Rain clouds

Chaff

Sea Echo,
high wind

Wooded
Hills, 20
mph wind

Sparse Hills,
Calm wind



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

n
n

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

n
n

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Internal Fluctuation of Clutter:

The power spectra expressed in the three parameters are:

$$1. \quad W(f) = |g(f)|^2 = |g_0|^2 \exp \left[-a \left(\frac{f}{f_0} \right)^2 \right]$$

"
n

$$2. \quad W(f) = W_0 \exp \left[\frac{-f^2}{2\sigma_c^2} \right]$$

n

$$3. \quad W(f) = W_0 \exp \left[\frac{-f^2 \lambda^2}{8\sigma_v^2} \right]$$

n

Moving Target Indicator Radar (MTI) Limitations of MTI

Clutter Attenuation

Performance

The definition of Clutter Attenuation is:

$$CA = \frac{\int_0^{\infty} W(f) df}{\int_0^{\infty} W(f) |H(f)|^2 df}$$

The frequency response of a single delay line filter is

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

Moving Target Indicator Radar (MTI) Limitations of MTI

Clutter Attenuation

Performance

The definition of Clutter Attenuation is:

$$CA = \frac{\int_0^{\infty} W(f) df}{\int_0^{\infty} W(f) |H(f)|^2 df}$$

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

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

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

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

n

n

Moving Target Indicator Radar (MTI) Limitations of MTI Performance

Clutter Attenuation

Note that

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

Thus

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

and

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

Moving Target Indicator Radar (MTI) Limitations of MTI

Improvement Factor Performance

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

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

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

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

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 by $\left(\frac{\dot{\theta}_s}{\theta_B}\right)^2$

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

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

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

or

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

Moving Target Indicator Radar (MTI)

Limitations of MTI Performance

Antenna Scanning Modulation

Substituting into the equations for I_c ,

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

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

n

n

n

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
- Tracksmoothing
- Tracktermination

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 n that pulse.

Thus theoretically the resolution is

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

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_n present

e.g. targets for two scans and two targets

n



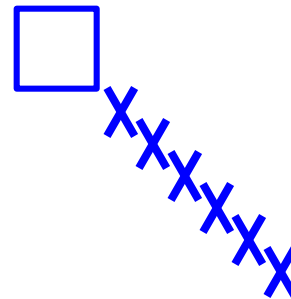
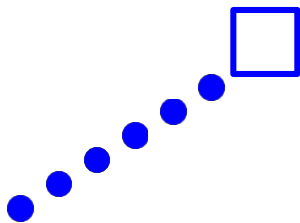
Tracking with Scanning Radars (Track While scan)

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



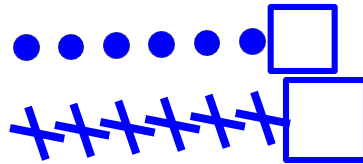
n

n

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

manoe

uvres

n

Gate size is made variable depending on

- Accuracy of track
- Expected acceleration of the target

Tracking with Scanning Radars

(Track

k While scan)

Automatic Detection and Tracking (ADT)

Track Smoothing

Predictions are based on track history

α - β Tracker

predicted

measured

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

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

Predicted position:

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

Unit IV

TRACKING RADAR AND RADAR DETECTION THEORY

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

Target tracking

Targets are divided to two types:

- 1 Single target
- 2 Multiple targets

Single target

1 Angle tracking

A- Sequential lobing B- Conical scan

C- Amplitude compression

monopulse D- Phase compression

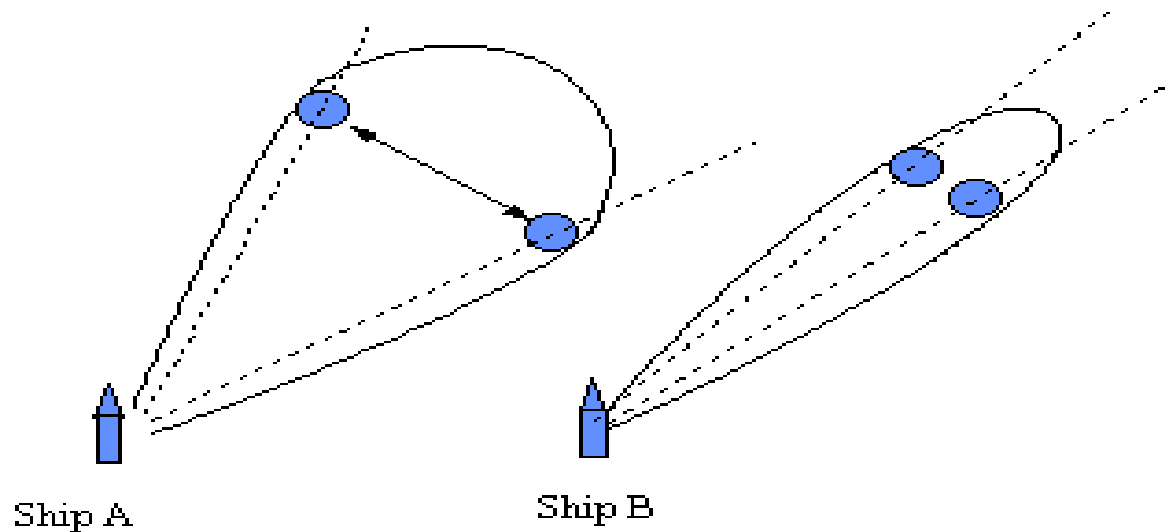
monopulse

2 Range tracking

Relation between beamwidth and accuracy

Antennas with wide beamwidth are less accurate than antennas with narrow

Beamwidth vs Accuracy



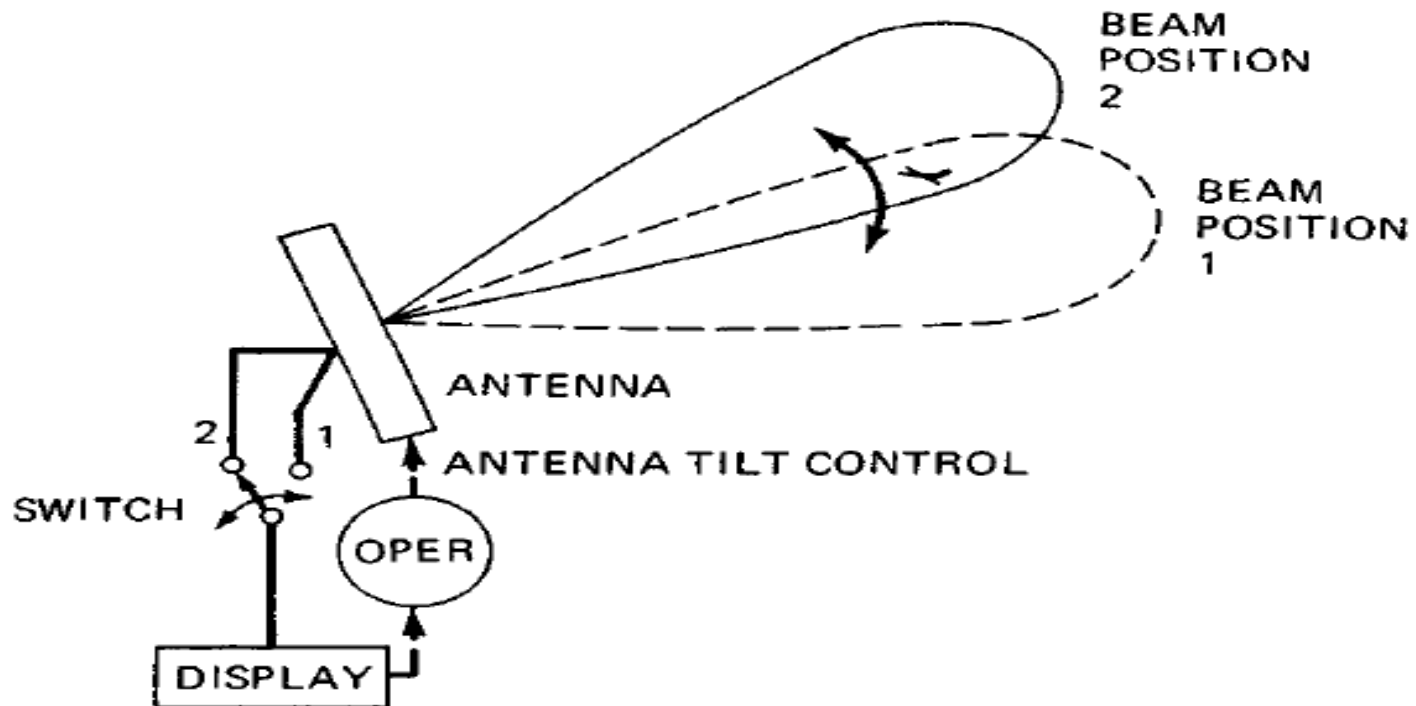
Pencil beam

In tracking processes radar used
narrower beams



Line of Sight (LOS) axis

The LOS is called the radar tracking axis too



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

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

SCR-268

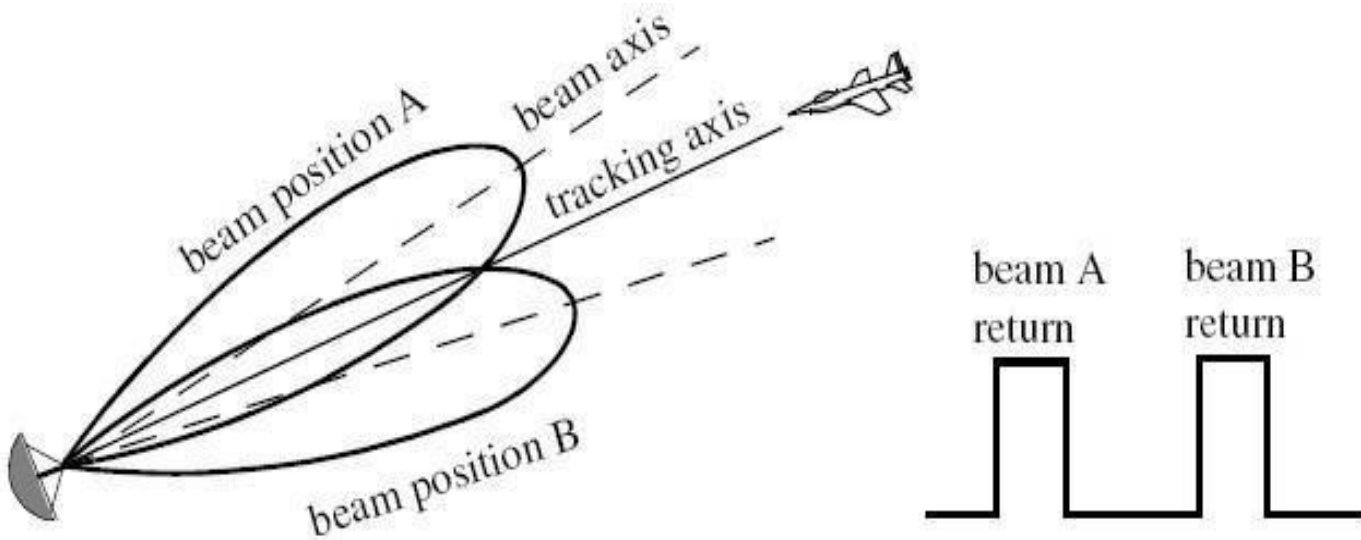


Concept of operation:

- Measuring the difference between the echo signals voltage levels

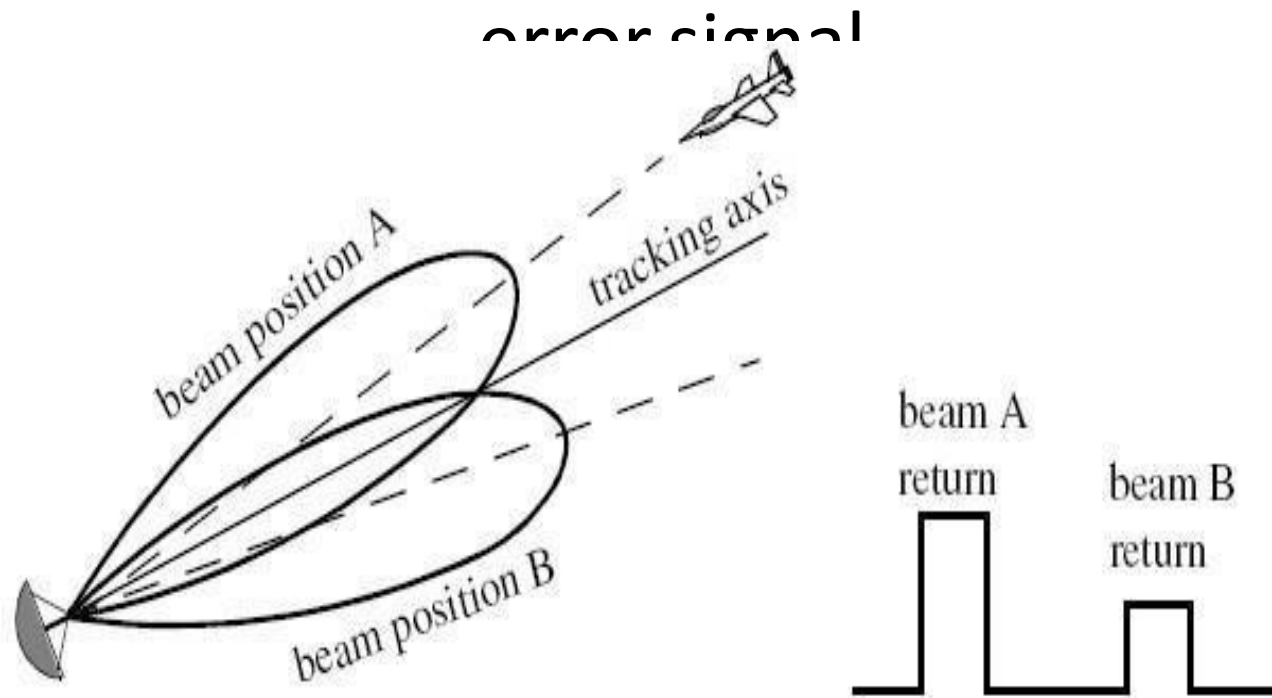
1- When the target being on the LOS

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

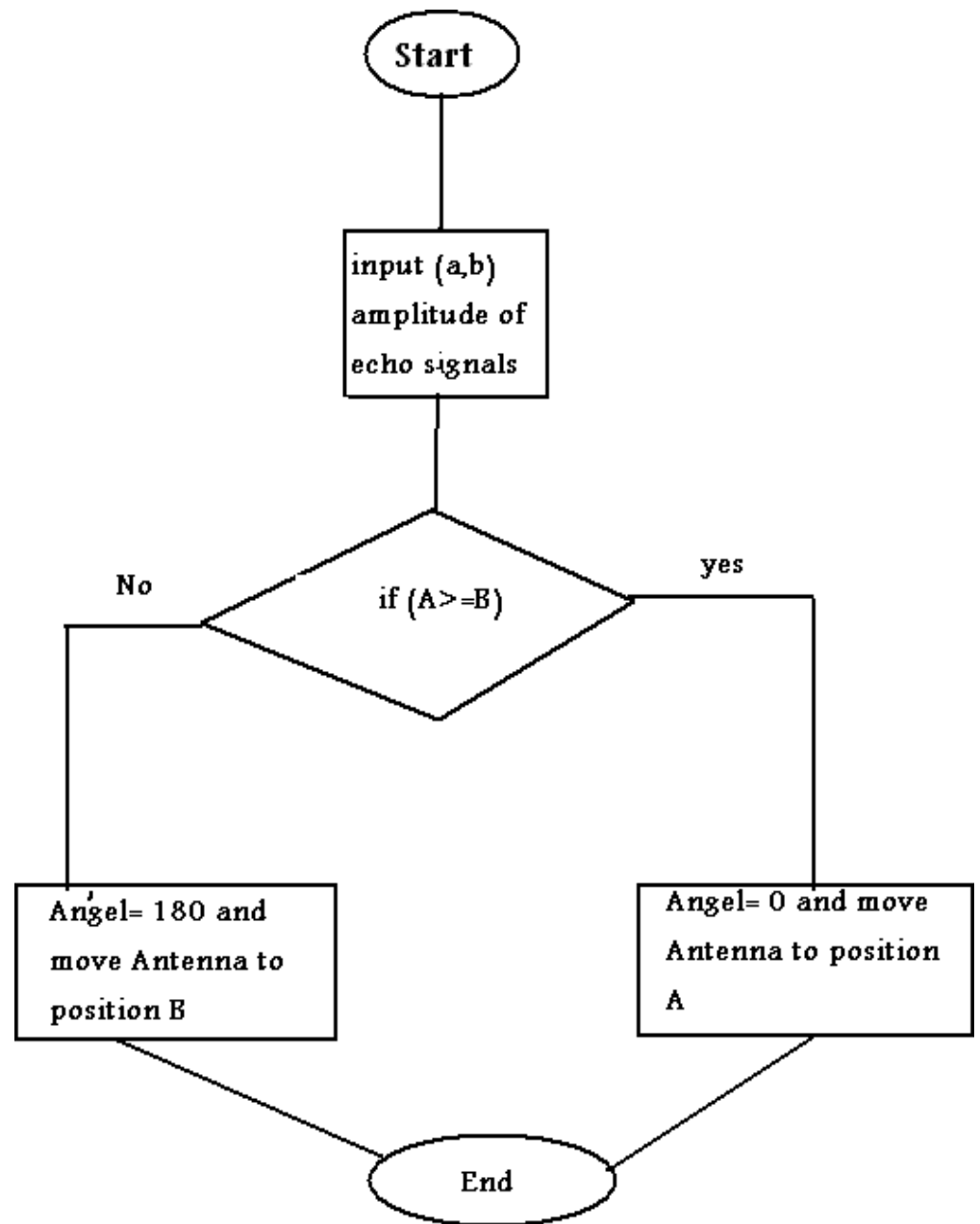


2. When the target being off the LOS

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

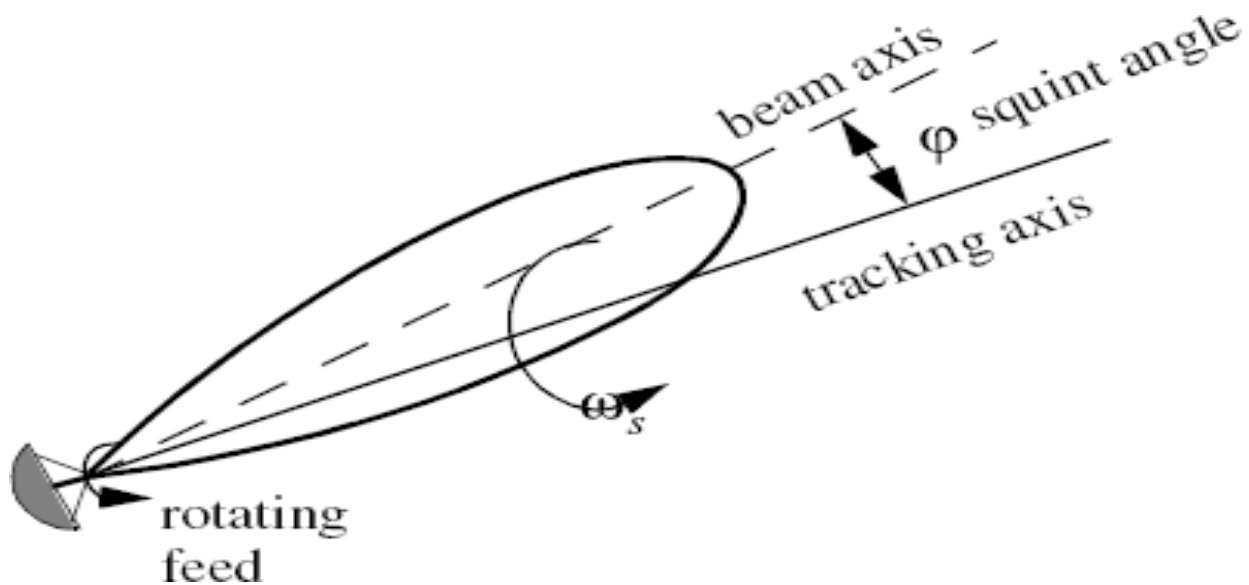


Mat lab Code

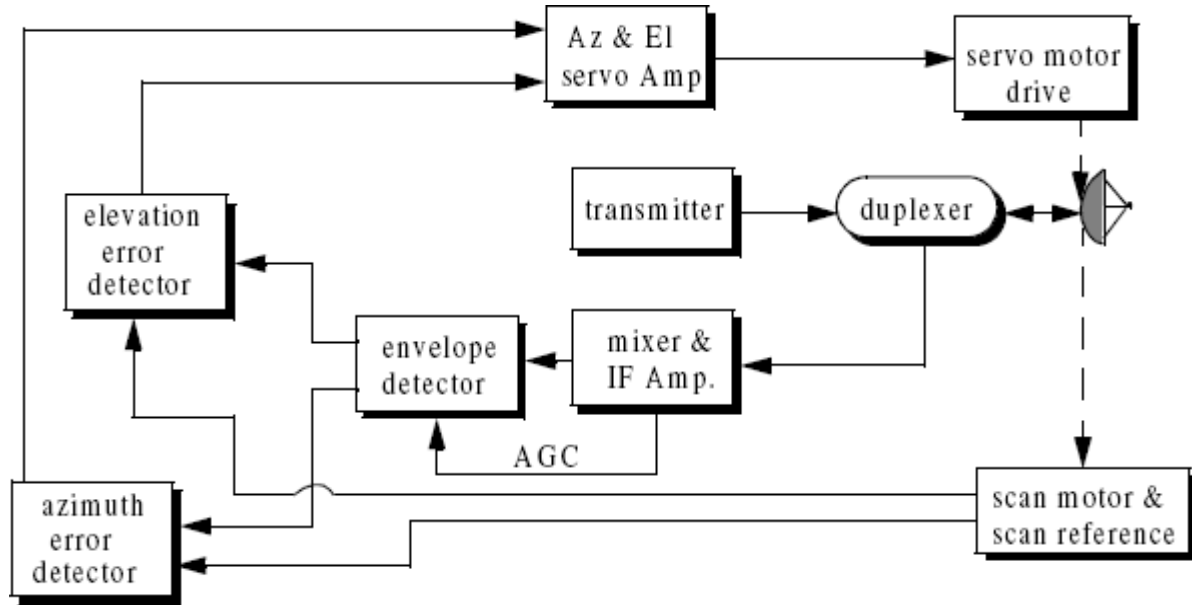


2. Conical scan

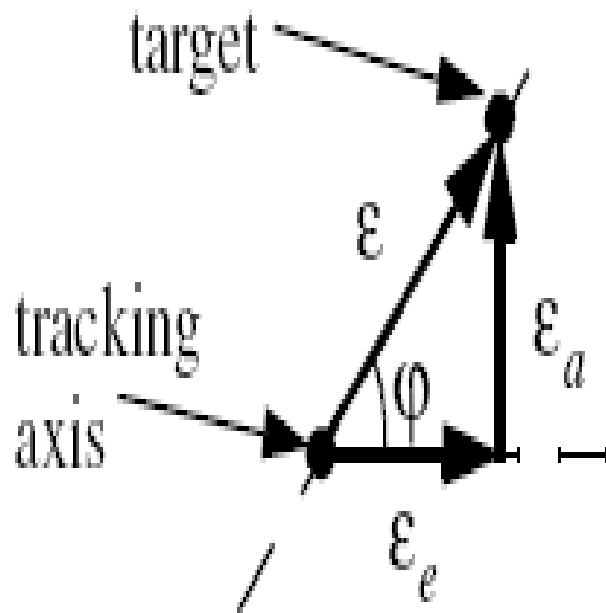
- It's an extension of sequential lobbing
- The feed of antenna is rotating around the antenna axis



- 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



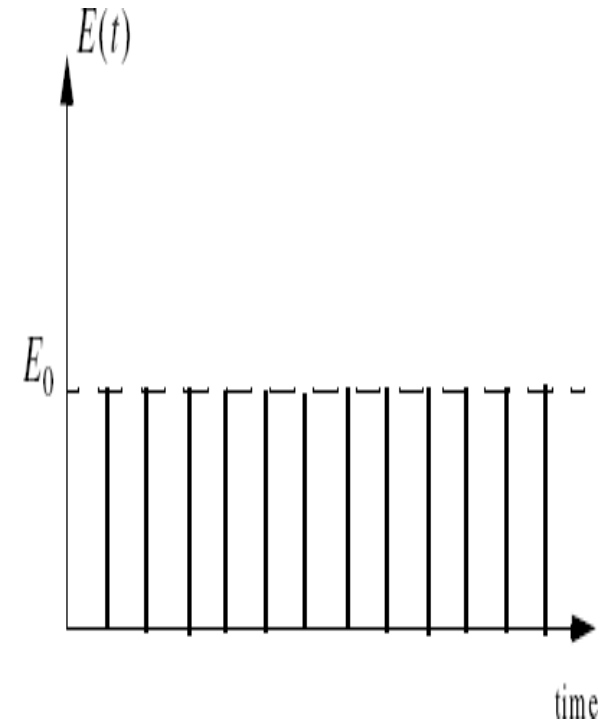
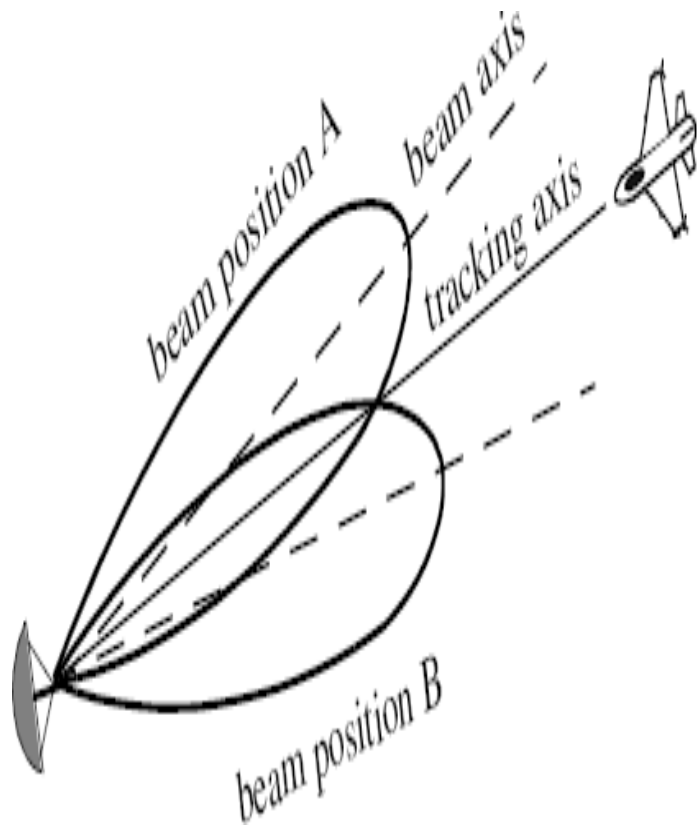
Elevation and azimuth error



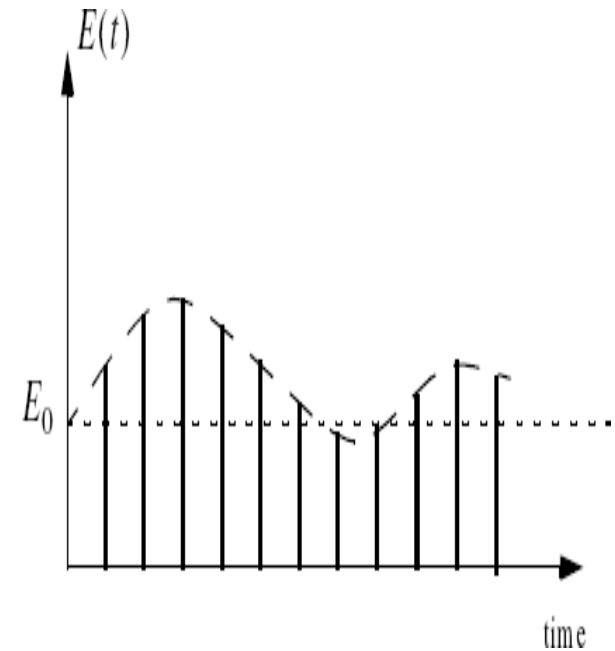
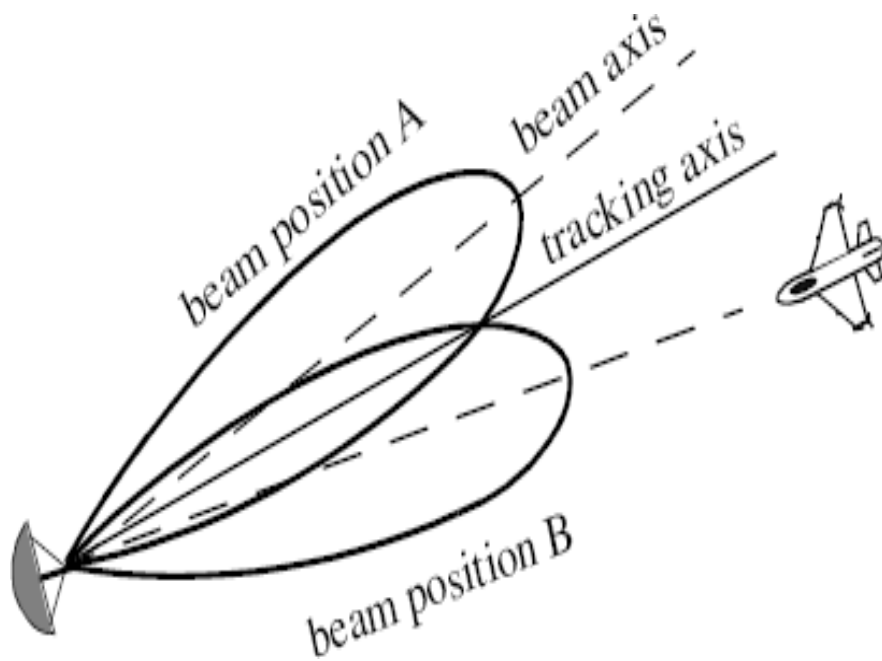
$$E_e(t) = -\frac{1}{2}E_0 \cos \phi$$

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

1- When the target being on the LOS



2. When the target being off the LOS

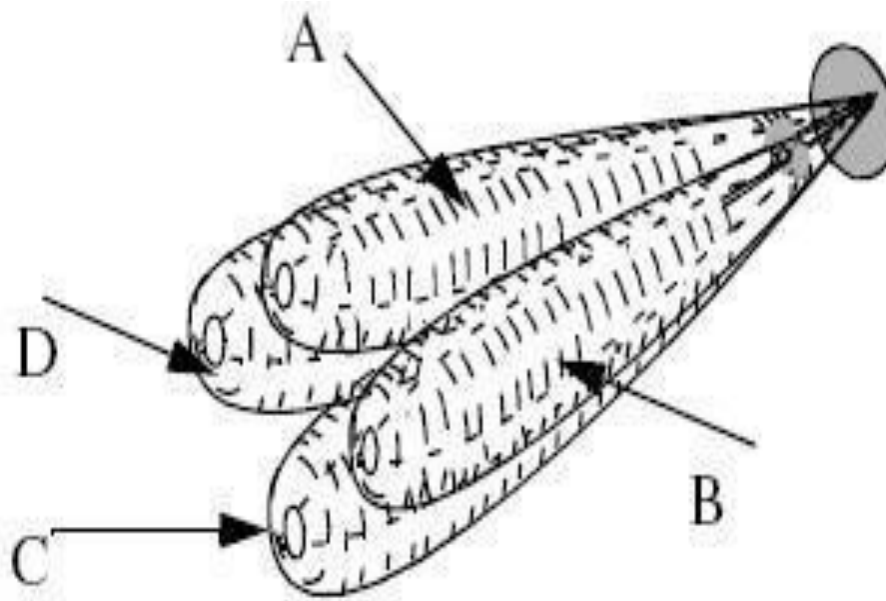


3. Amplitude compression monopulse

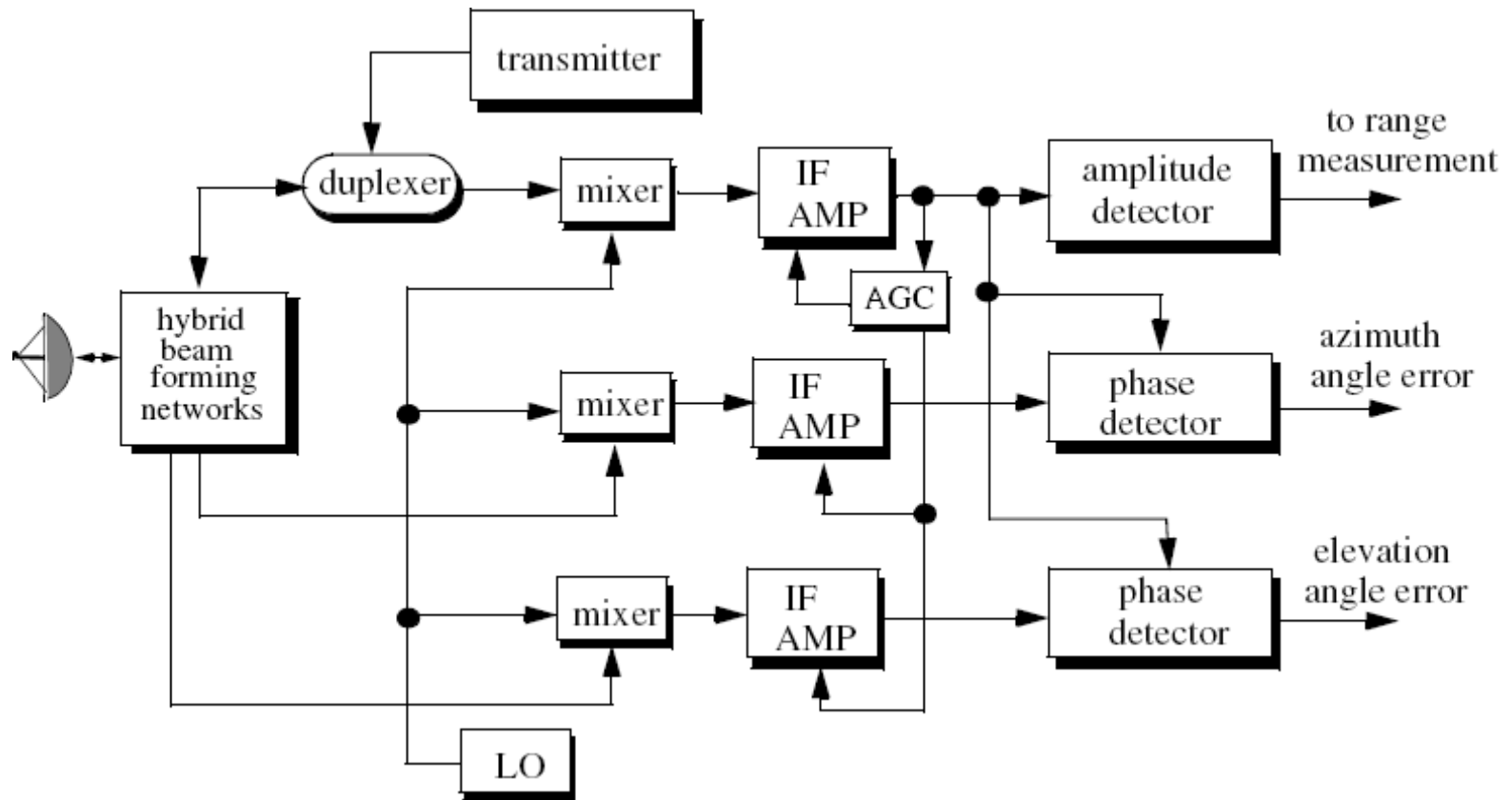
- This type is more accurate than sequential and conical scanning
- Feed generated four beams simultaneously with single pulse
- The four beams are inphase but have different amplitudes.

Four beams shape

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

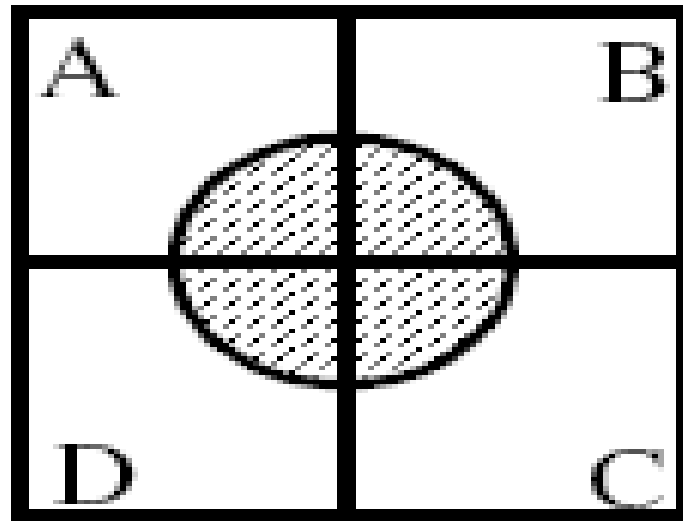


Simplified amplitude comparison monopulse radar block diagram

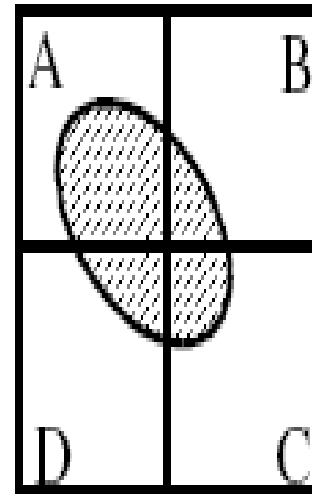
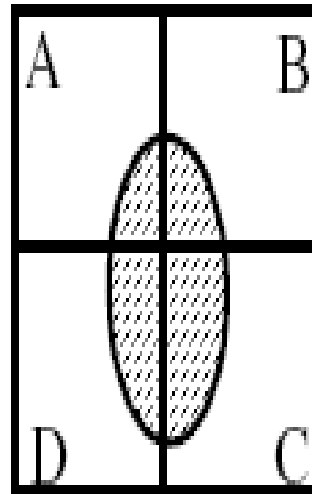
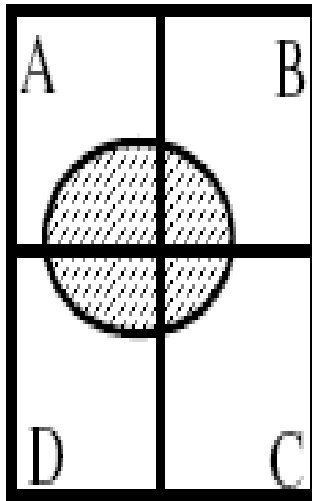


When the target being on the LOS

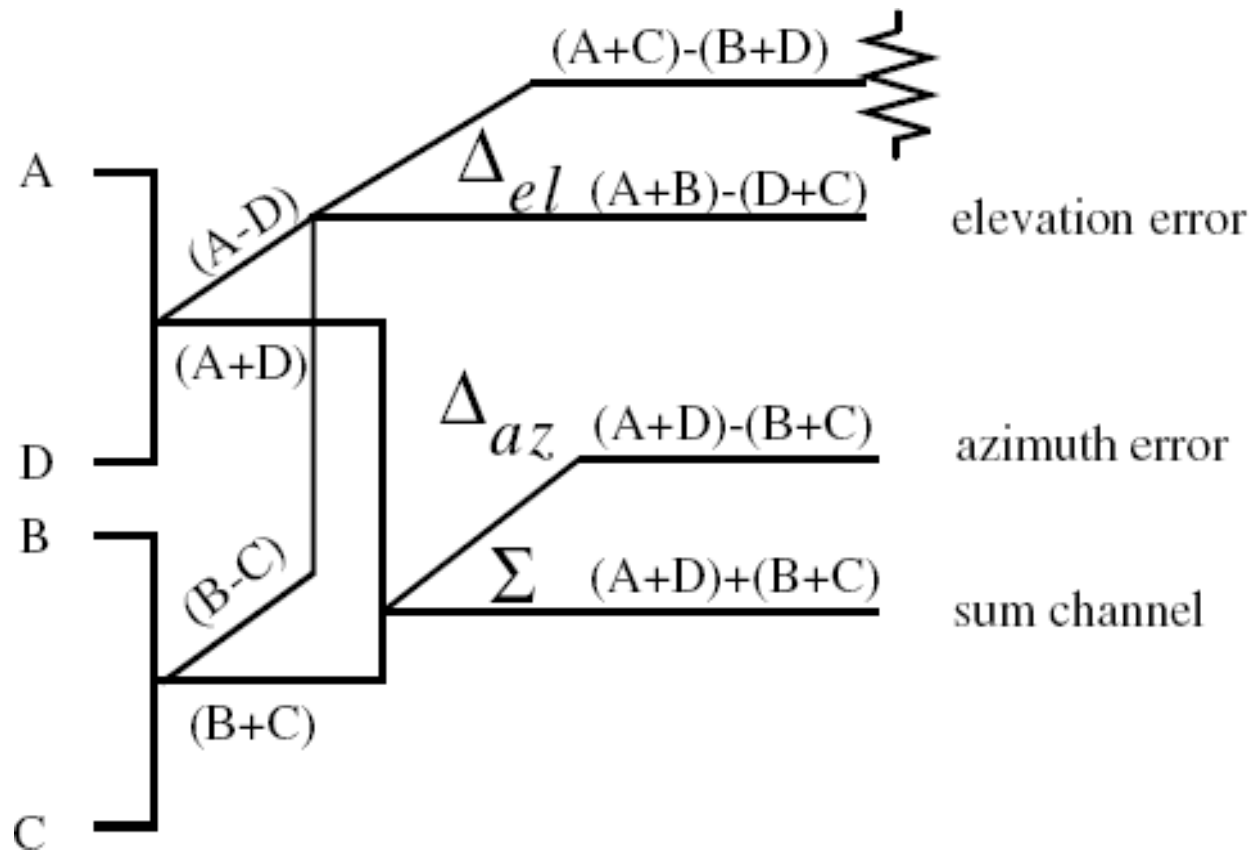
radar compares the amplitudes and phases of
all echo signals of target



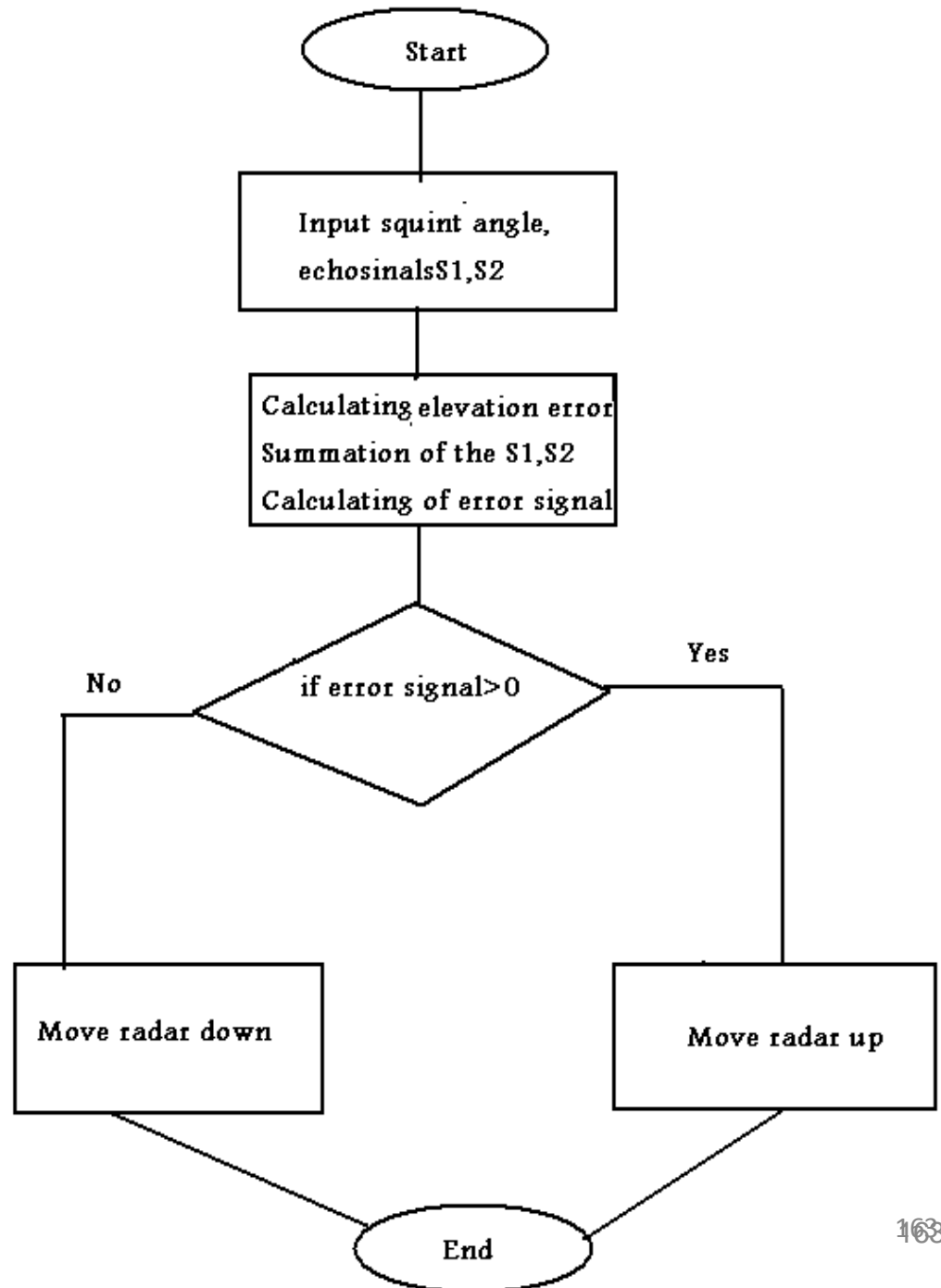
When the target being off the LOS



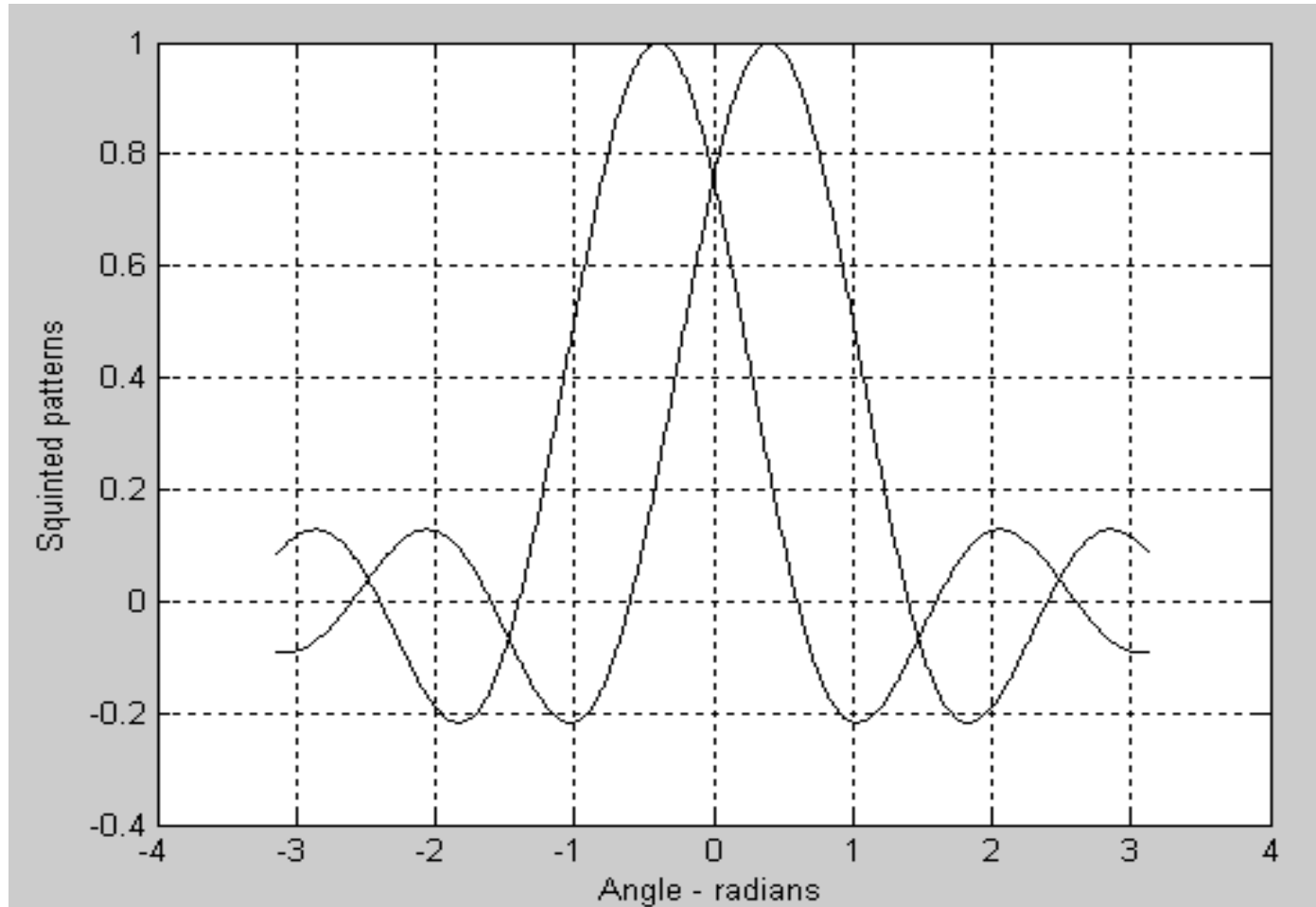
Microwave comparator circuitry



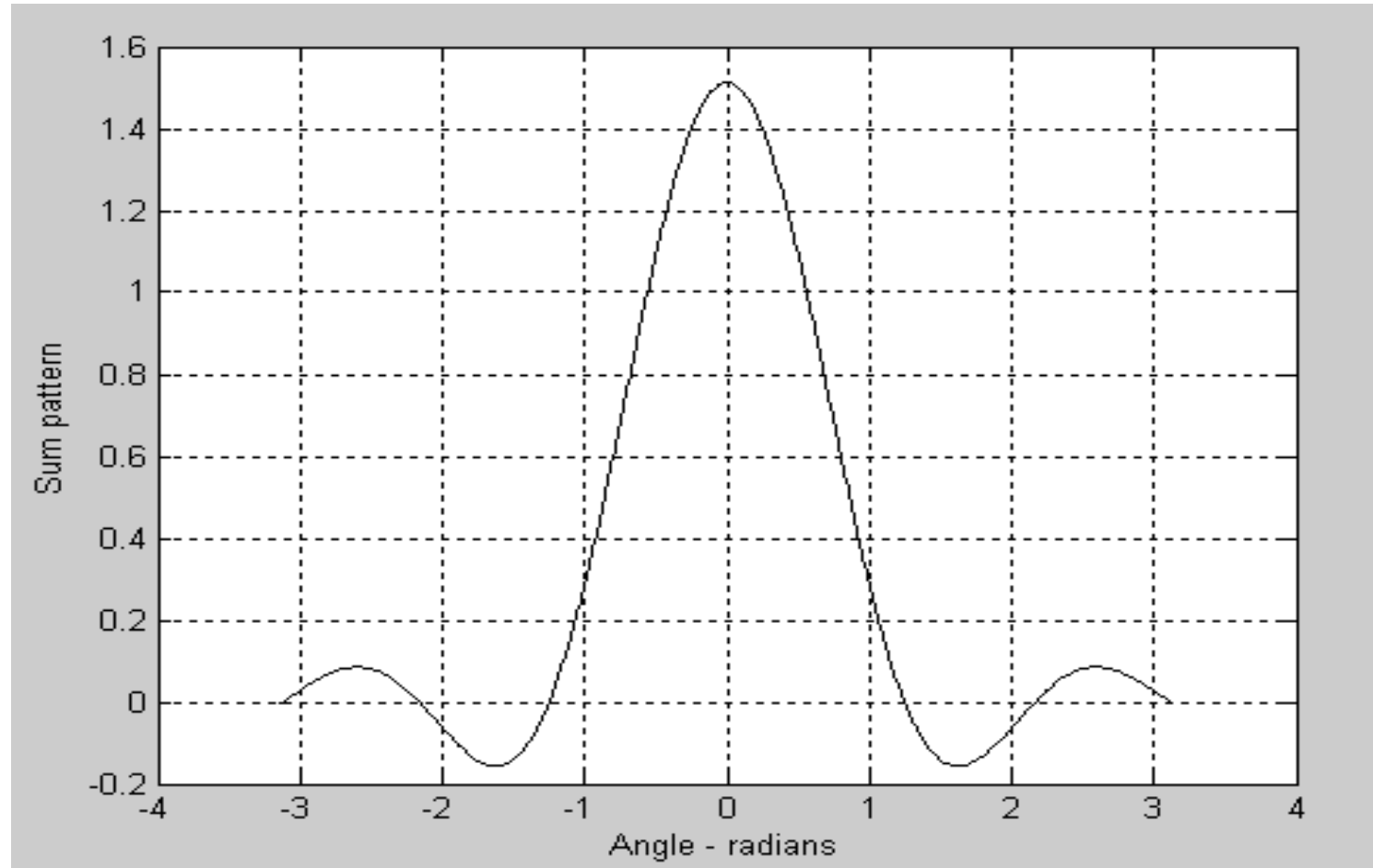
Mat lab code



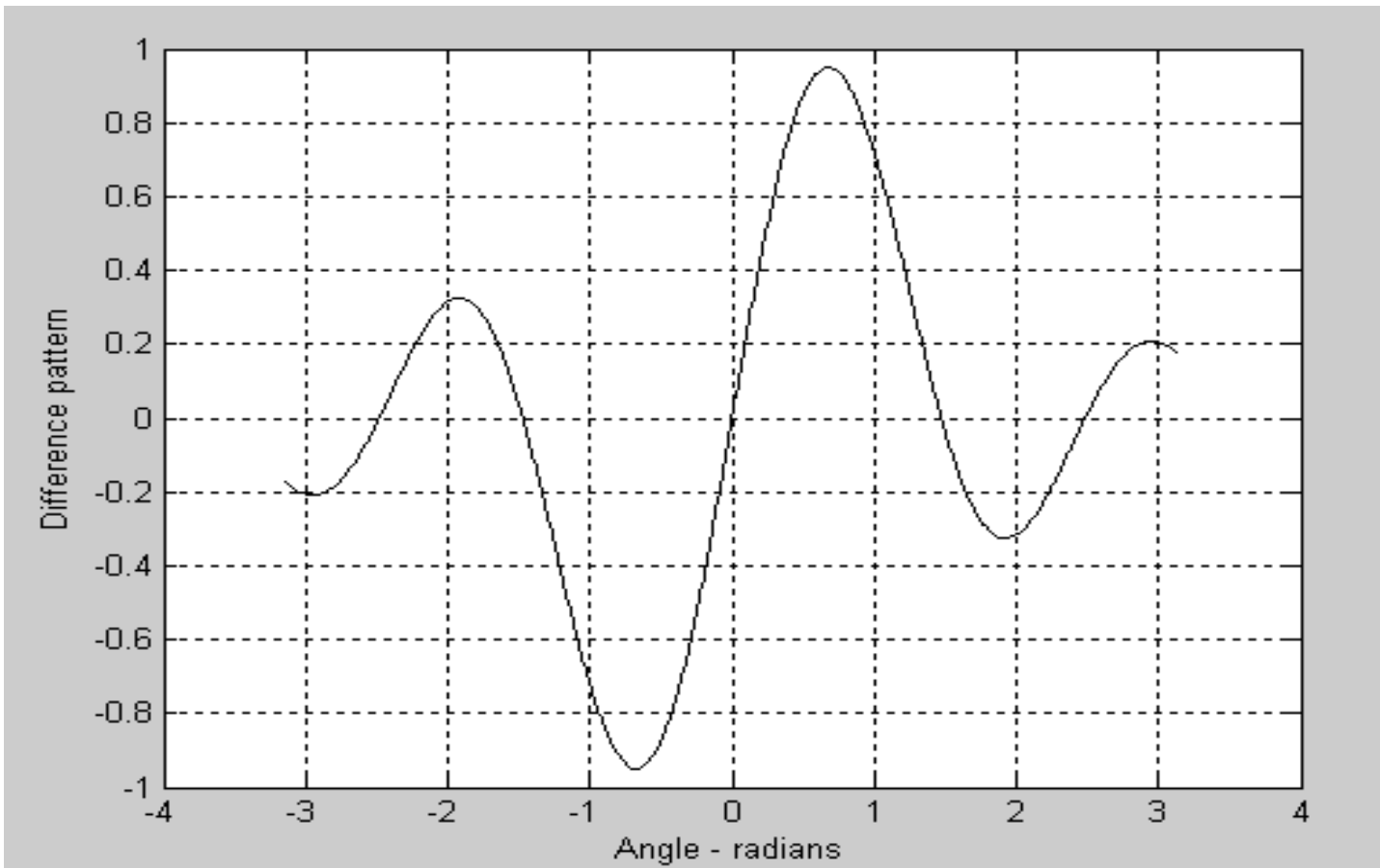
Two echo signals at squint angle angle ($\phi=0.4$ rad)



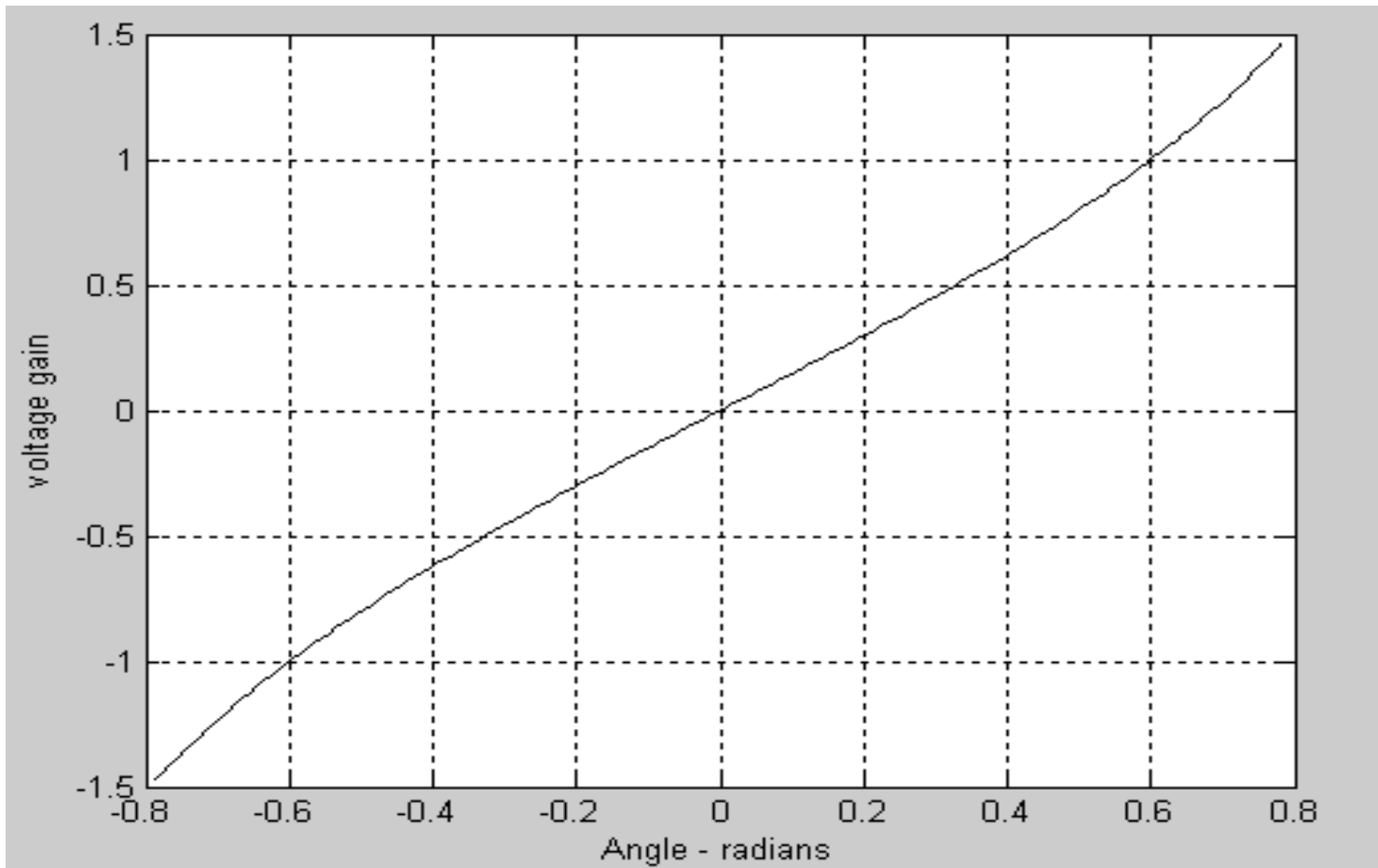
Sum of the two signals S1,S2



Difference between S1,S2



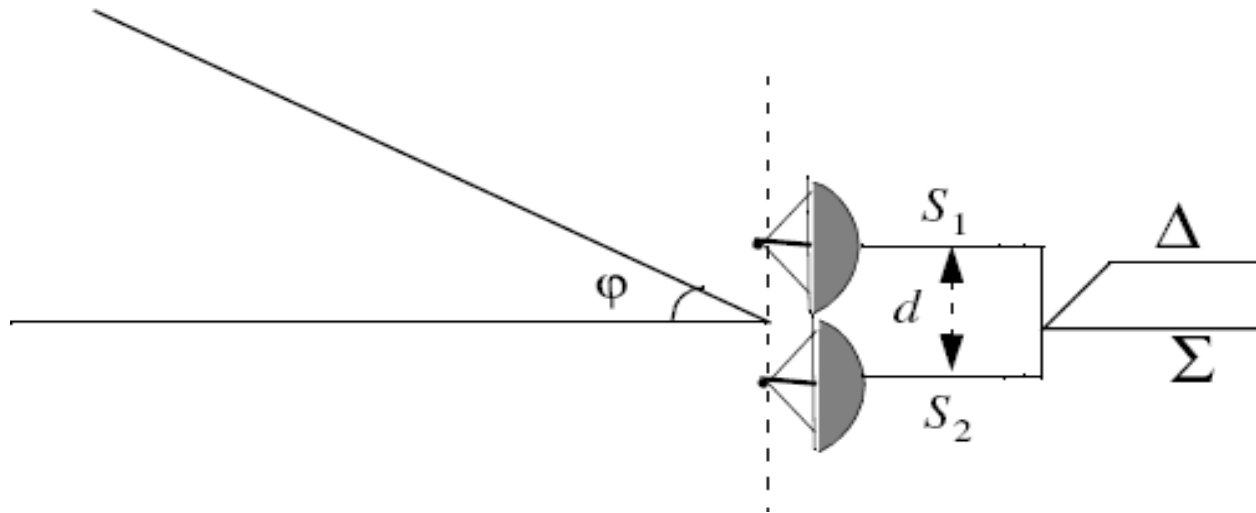
Elevation Error signal



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

Single coordinate phase monopulse antenna



$$\frac{|\Delta|}{|\Sigma|} = \tan\left(\frac{\phi}{2}\right)$$

Range tracking

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

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

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

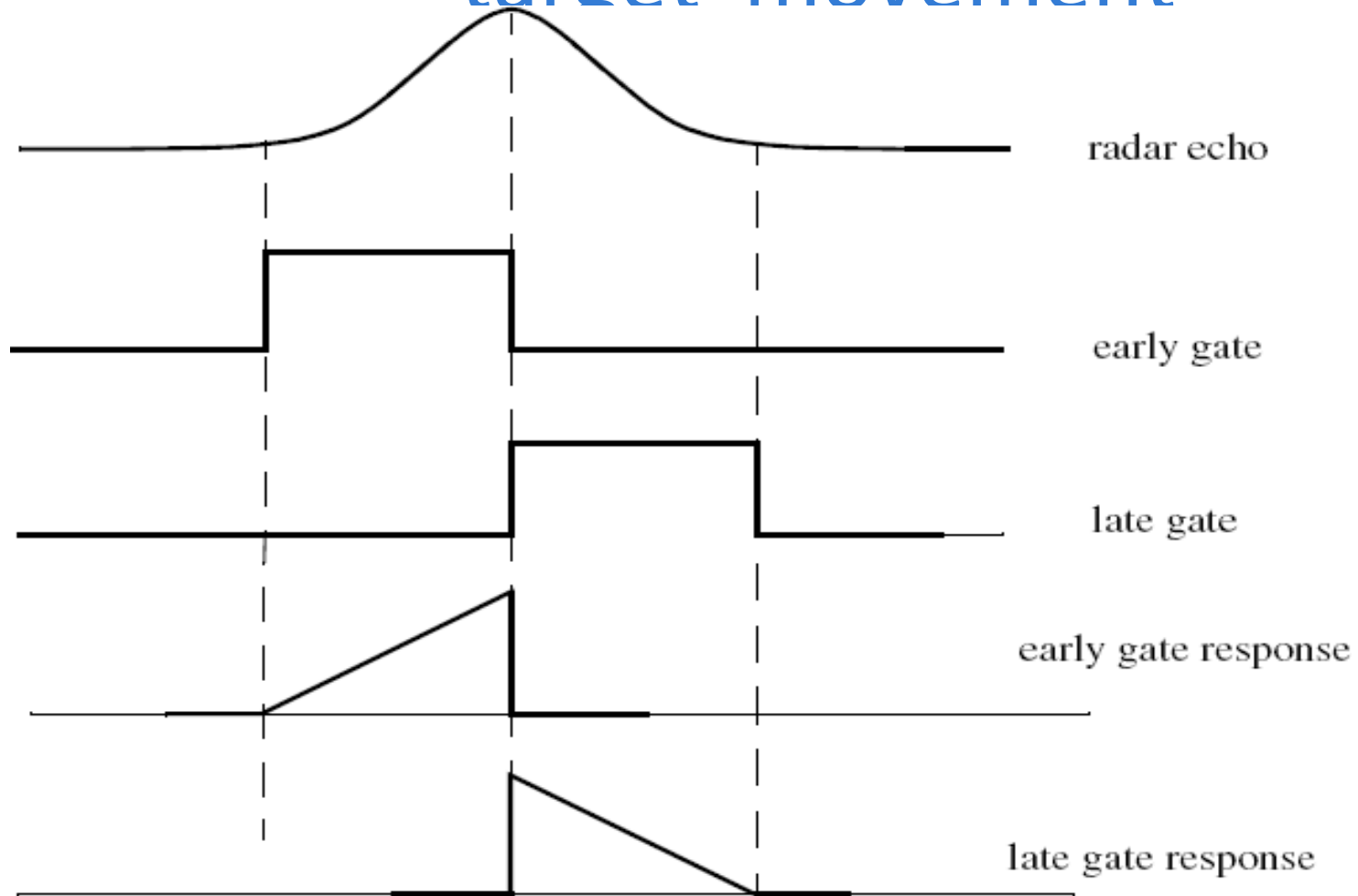
$T_R = \text{round-trip time, sec}$

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



Multiple Targets

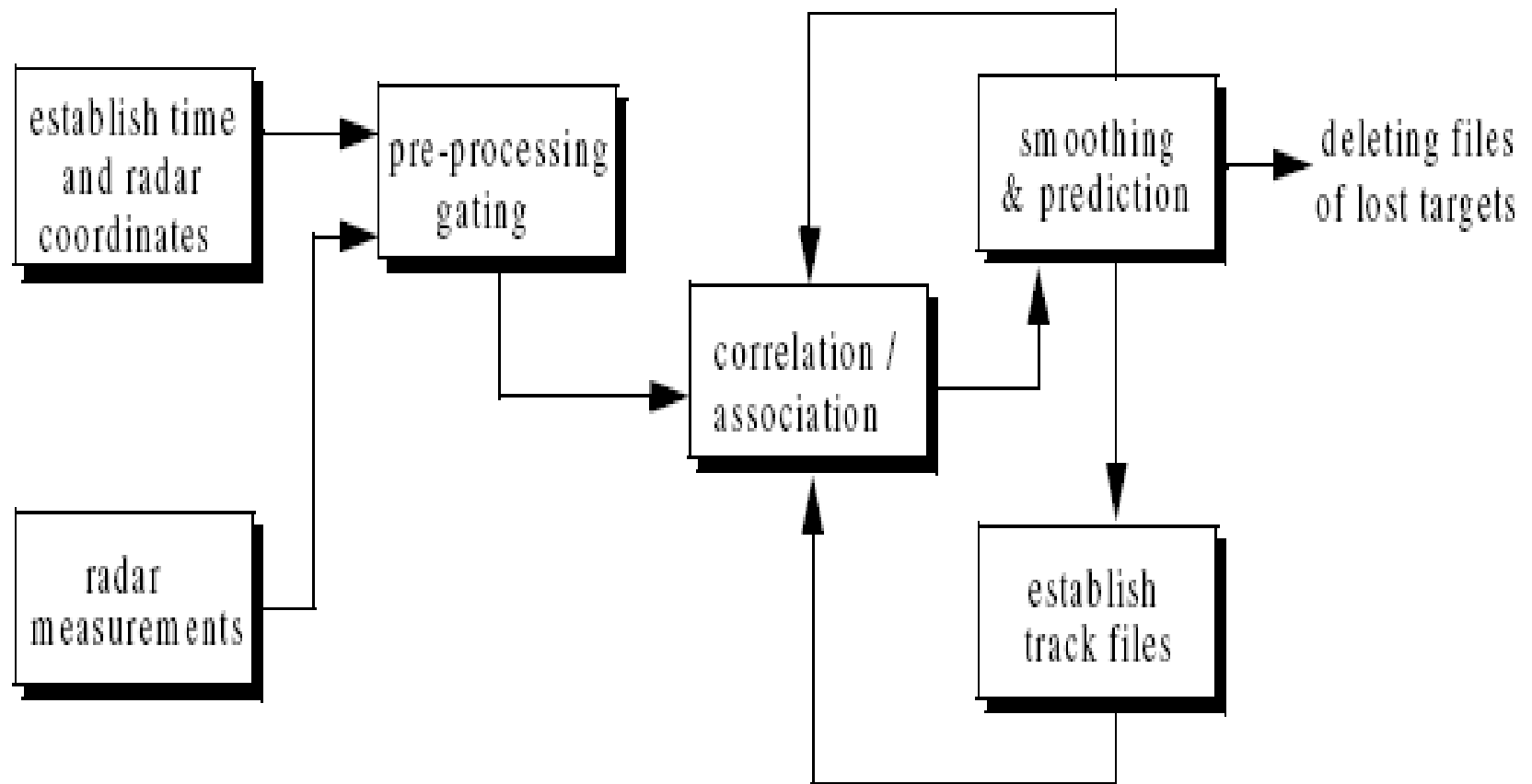
Here the system is more difficult since:

- Tracking
- Scanning
- reporting

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

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



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

Target Detection

This task is accomplished by two method :

- Circuit in receiver
- signal-processing equipment

Generation Gate

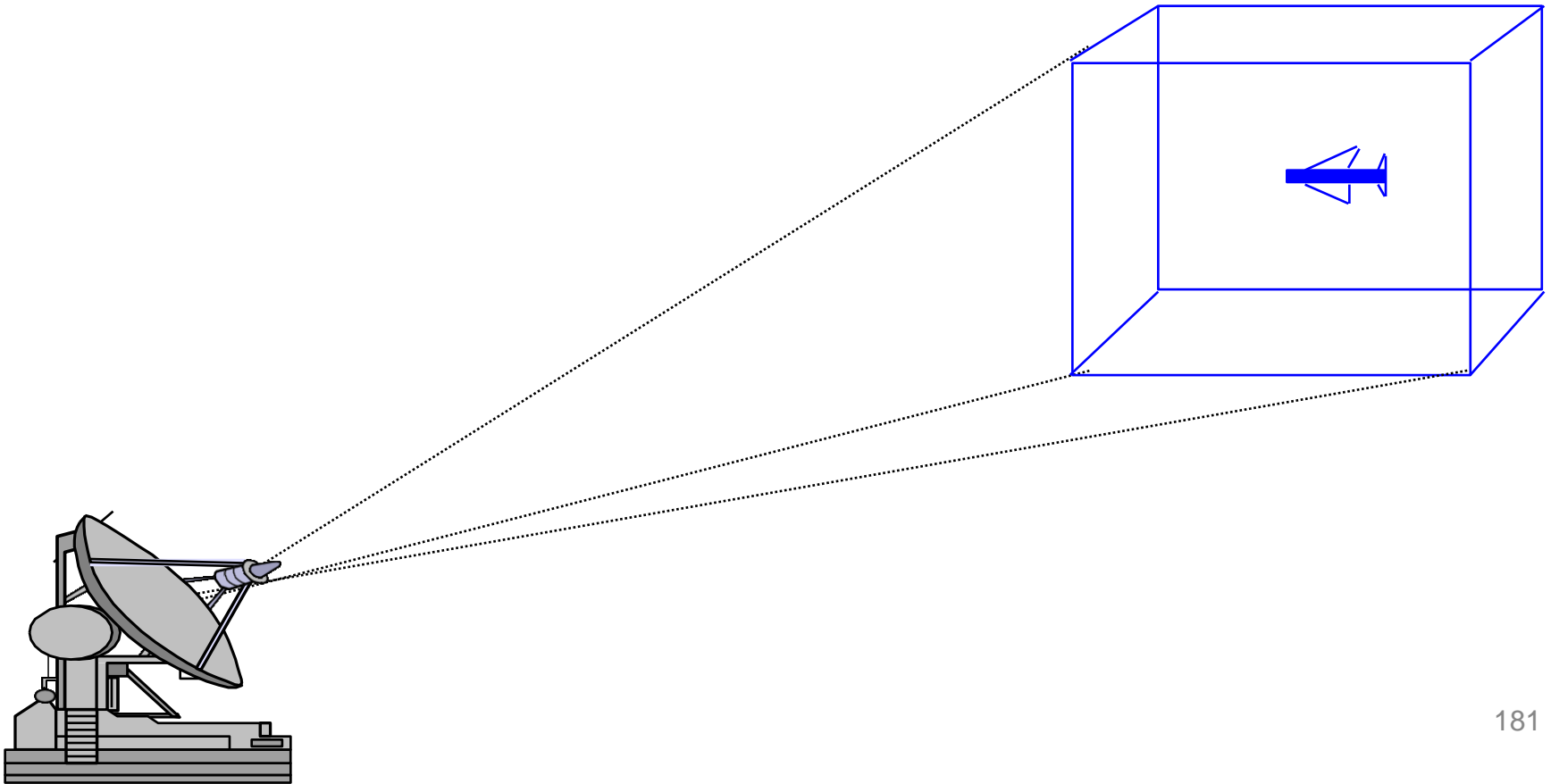
- Gate : small volume of space consist of many of cells
- Function : monitoring of each scan of the target information
- Gating has responsibility for knowing if new/exist target

Gate Types

- Acquisition gate
- Tracking gate
- Turning gate

Acquisition Gate

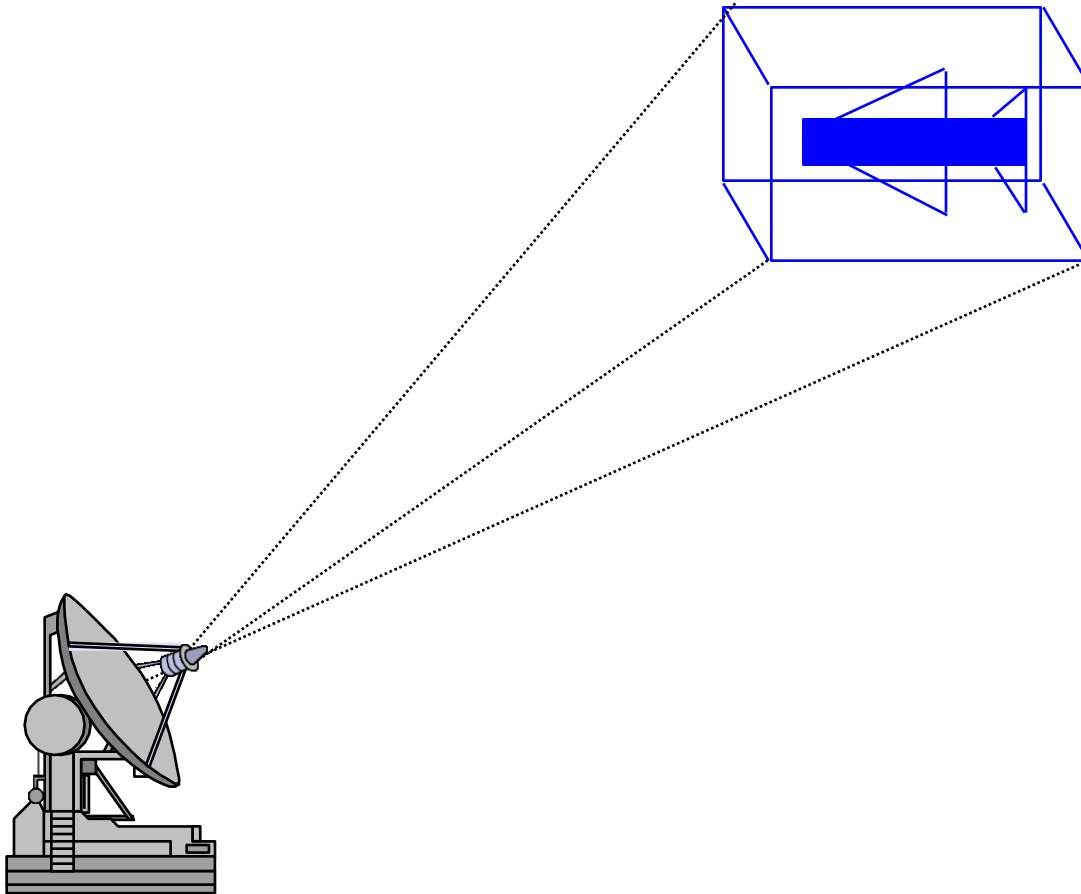
- This gate is large to facilitate target motion cross one scan period



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

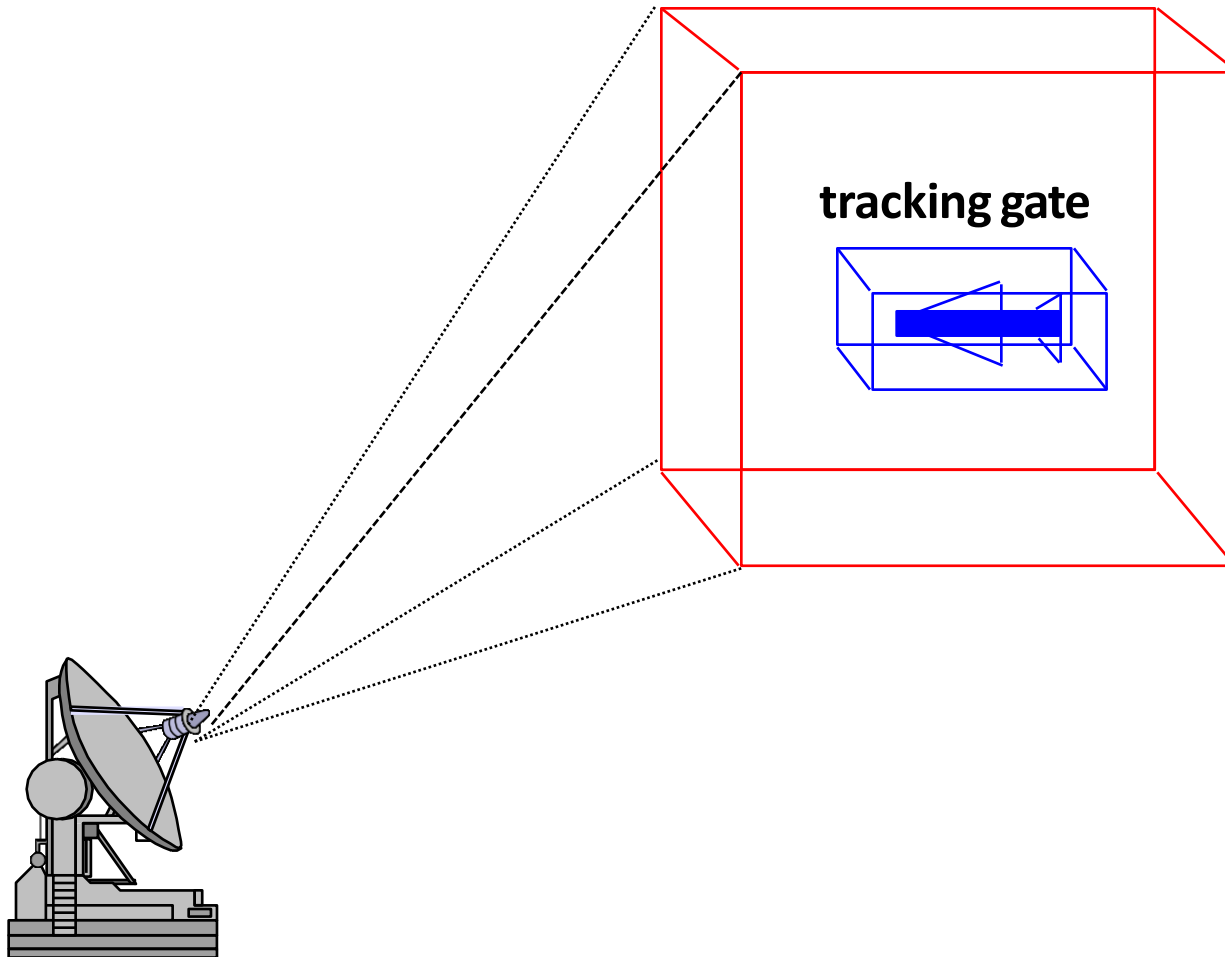
Tracking Gate



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

Turning gate



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

Tracking Ambiguity Results

- If the observation correlates with more than 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

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

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

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

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

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

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

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

or

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

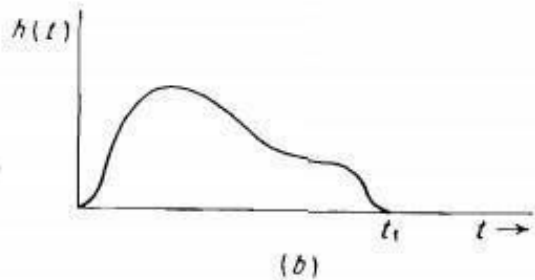
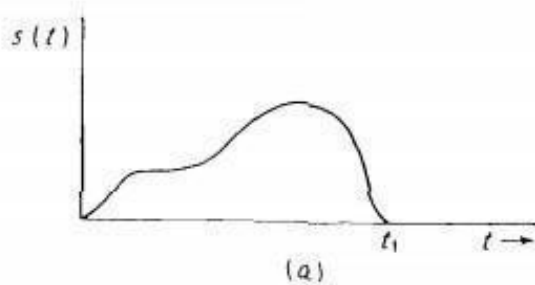
and

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

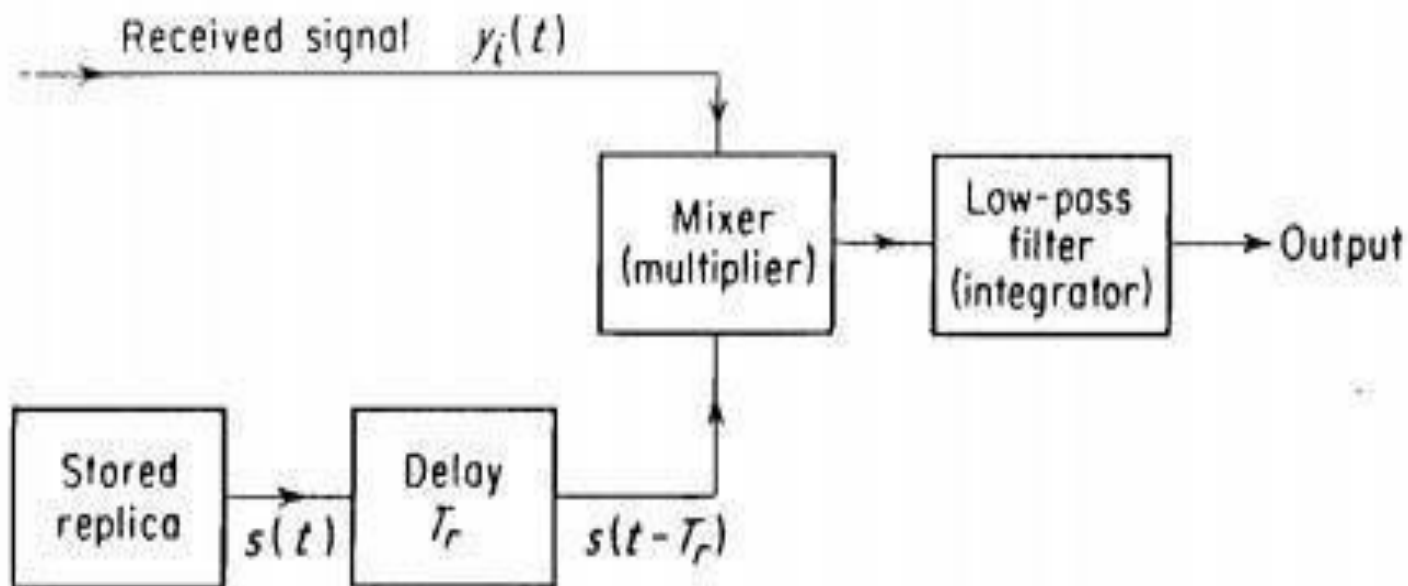
Derivation of the matched-filter characteristic:

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

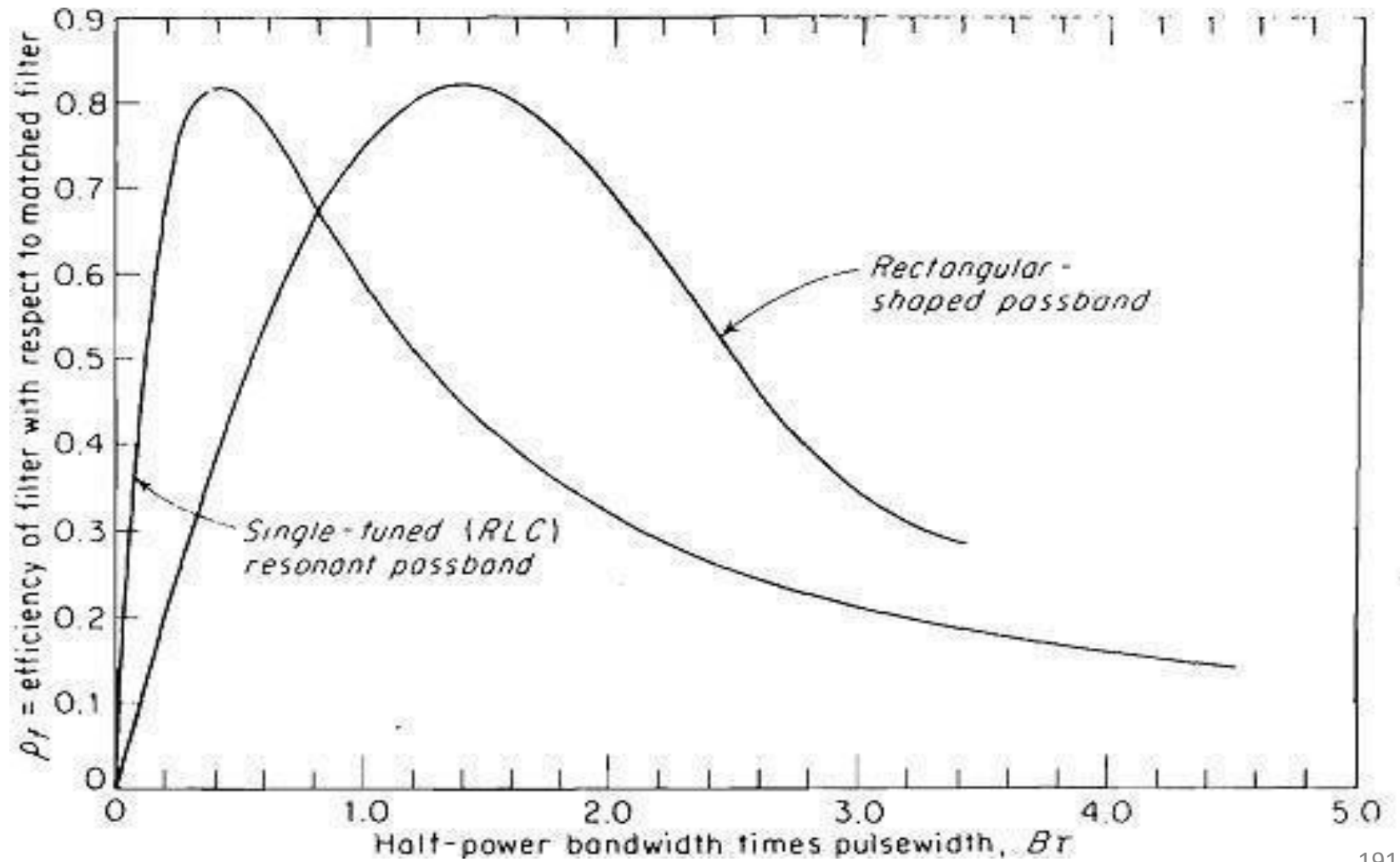
$$R_f = \frac{|s_o(t)|_{\max}^2}{N}$$



Correlation function and cross correlation receiver



EFFICIENCY OF NON-MATCHED FILTERS



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

Matched filter with nonwhite noise:

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

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

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 $S(f)/N_i(f)$.

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noi

Unit V

RADAR RECEIVERS



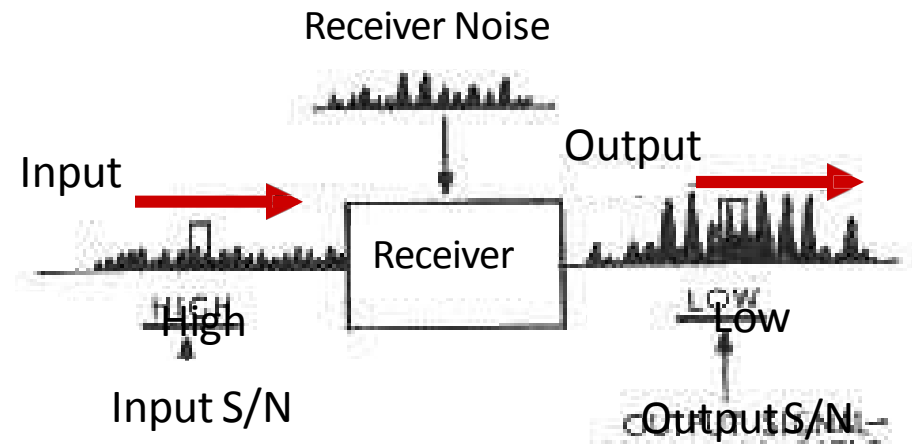
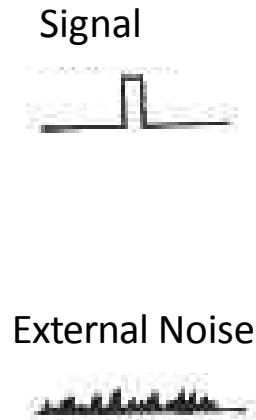
Pulse radars transmit a burst of energy and listen for echoes between transmissions.

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

Not occur at the receiving time

The received signal is usually heavily corrupted by:

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



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

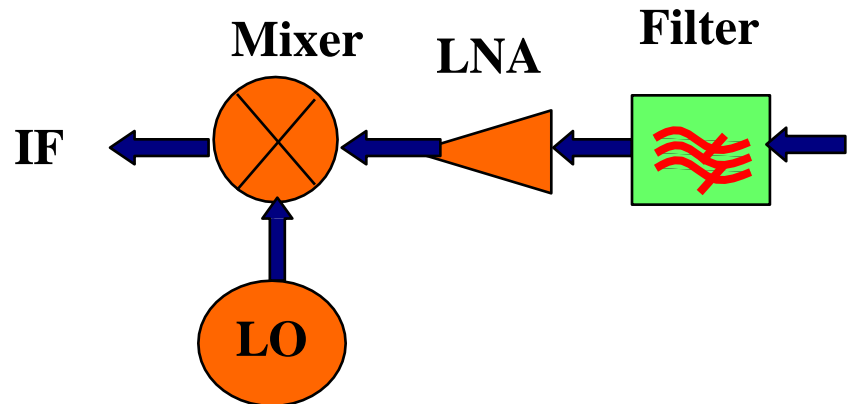
Oscillator

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.

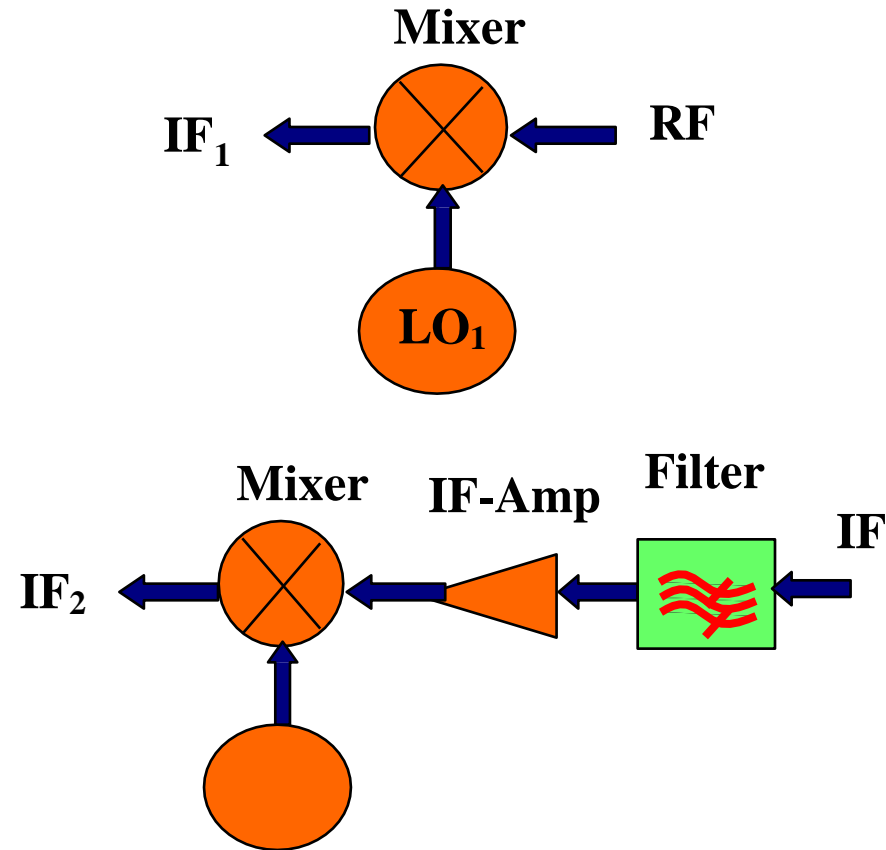
Tuning of the receiver, between the limits set by the **preselector** or **mixer bandwidth**, is accomplished by **changing the LO frequency**

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



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)

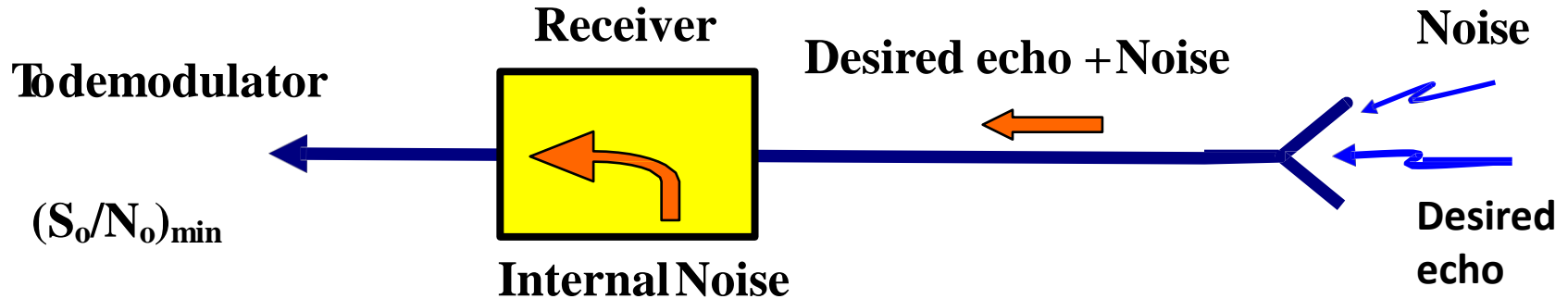
In airborne radars are used for altimeters or mapping:

- 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 signal 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

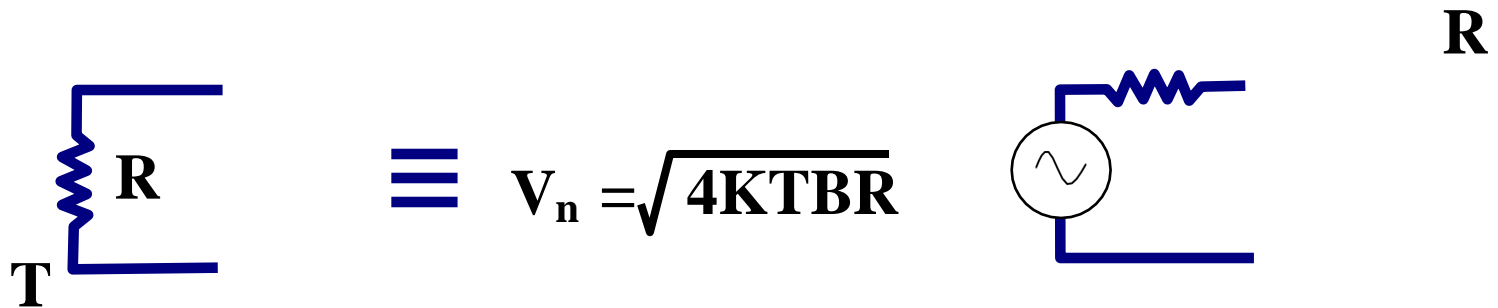
Filters: will filter noise

Attenuators: will attenuate

noise

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

At room temperature 290 K: **Band width in Hz:**

For 1 Hz band width,

$$P_n = -174 \text{dBm}$$

For 1 MHz Bandwidth

$$P_n = -114 \text{dBm}$$

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:

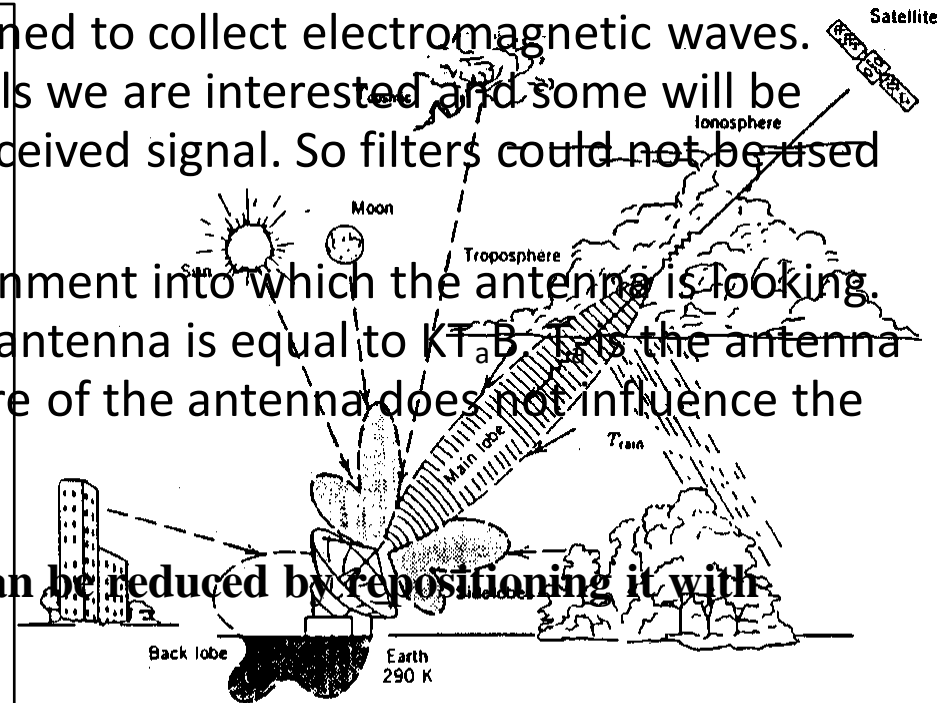
Recombination noise is the random generation and recombination of holes and electrons inside the active devices due to thermal effects. When a hole and electron combine, they create a small current spike.

Antenna Noise

In a receiving system, antenna positioned to collect electromagnetic waves. Some of these waves will be the signals we are interested 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 $K T_a B$. T_a is the antenna temperature. The physical temperature of the antenna does not influence the value of T_a .

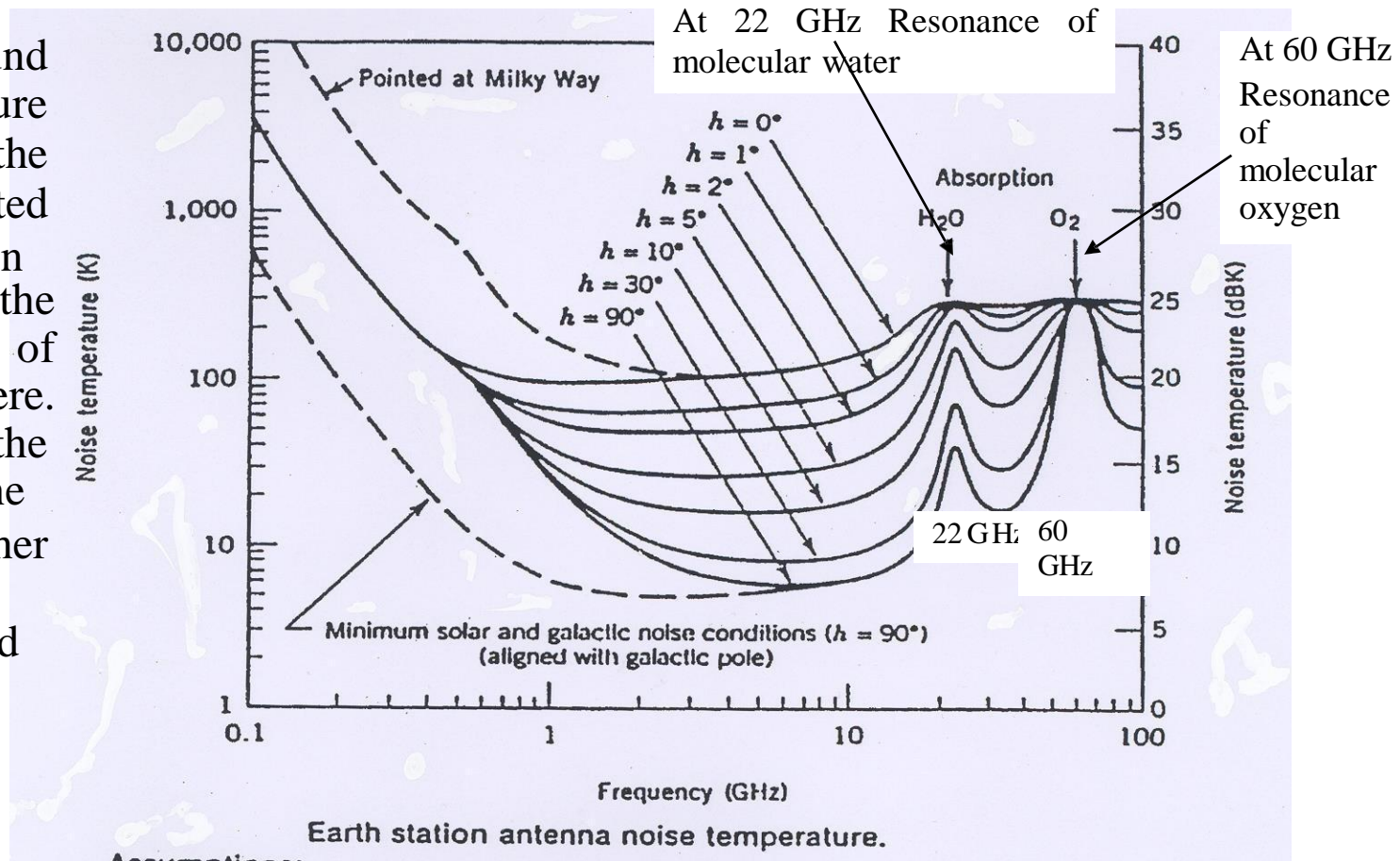
The noise temperature of the antenna can be reduced by repositioning it with respect to sources of external noise



Antenna noise temperature pickup

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

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

Equivalent Noise Temperature and Noise Figure

Noise Figure (F)



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

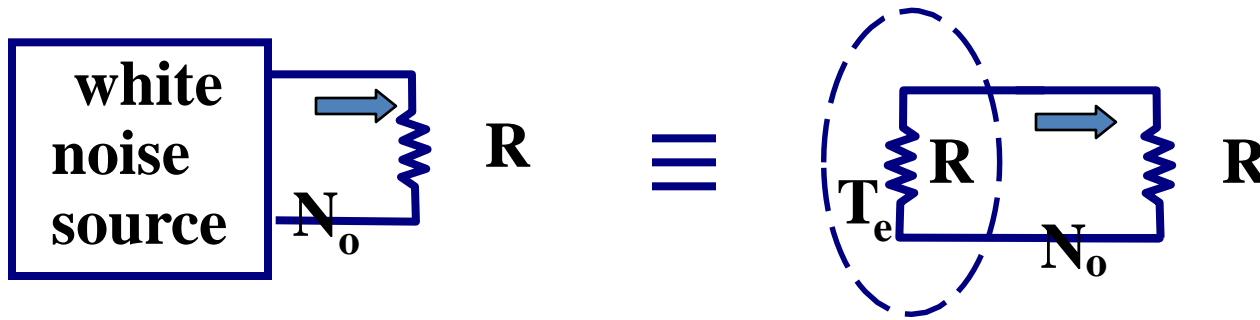
N_i = Noise power from a matched load at $T_0 = 290$ K; $N_i = KT_0 B$.

F is usually expressed in dB

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

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 .



$$T_e = N_o / KB,$$

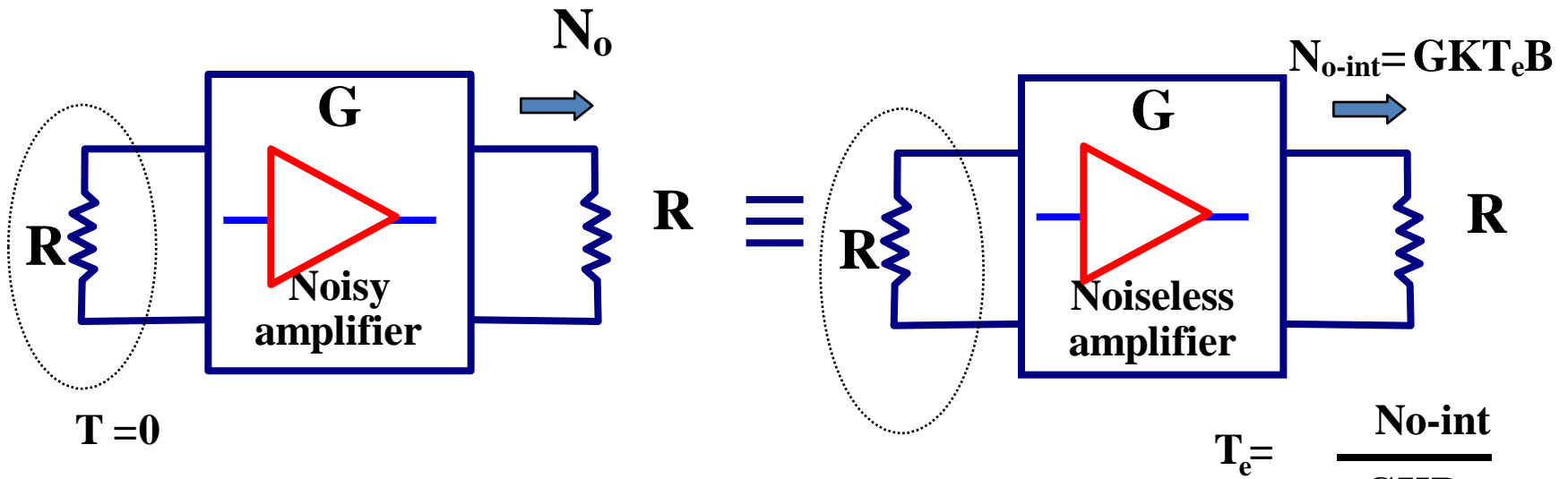
B is generally the bandwidth of the component or system

$$T_e \geq 0$$

If T_0 is the actual temperature at the input port, usually 290 K

T_e may be greater or less than 290K

Output Noise due to the internal noise of the receiver



$$T = 0$$

$$N_o = N_{o-int} + FGK T_0 B = GK T_e B$$

$$T_e = T_0(F - 1)$$

$$+ KT_0 B$$

$$G$$

$$F = \frac{T_e}{T_0} + 1$$

$$T_e = \frac{N_{o-int}}{GKB}$$

Noise Figure of Cascaded Components



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

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

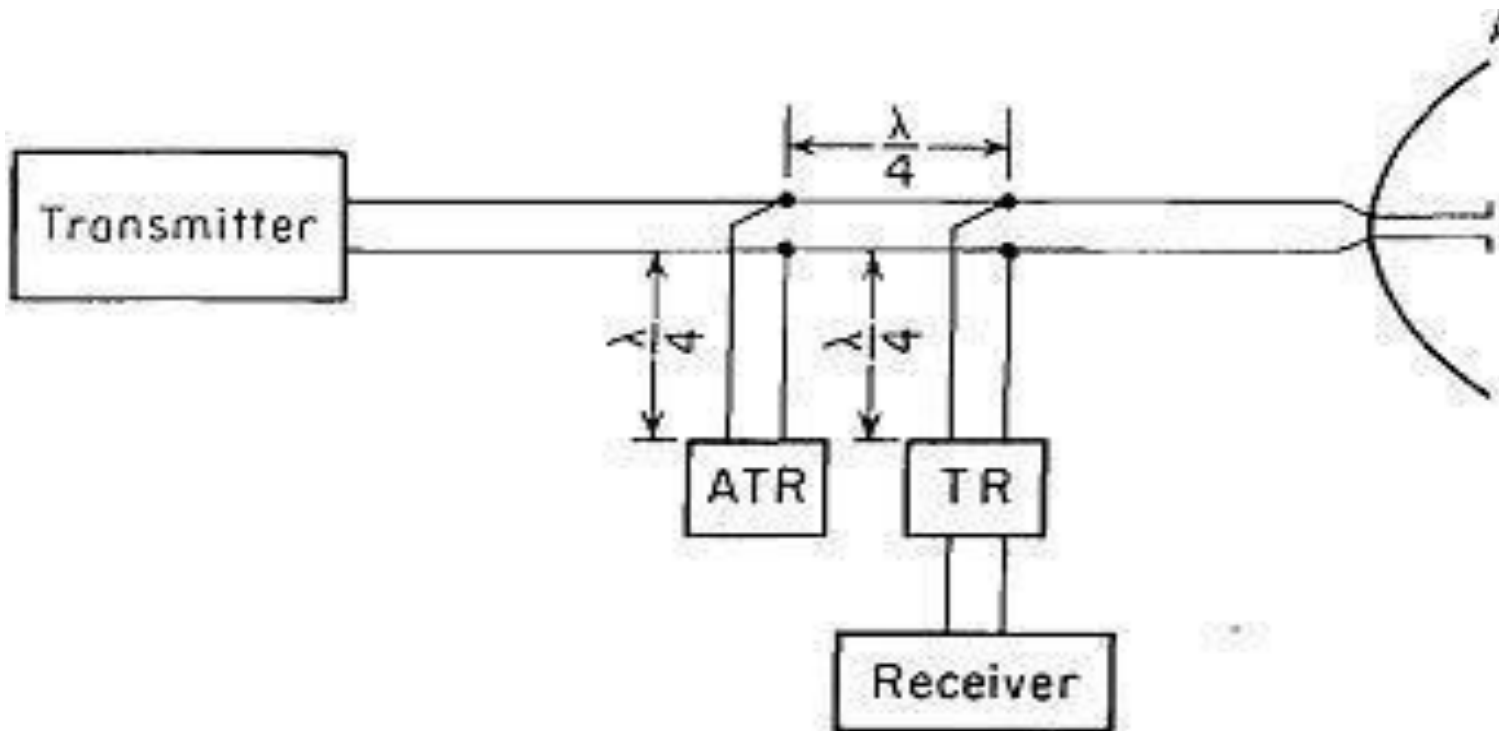
$$T_s = T_a + T_e$$



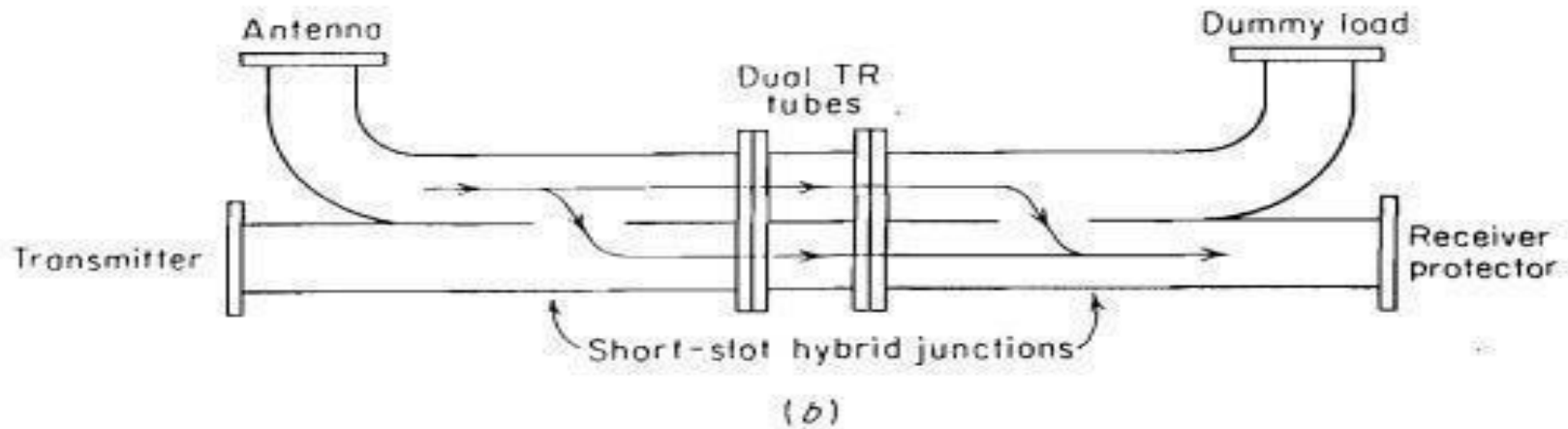
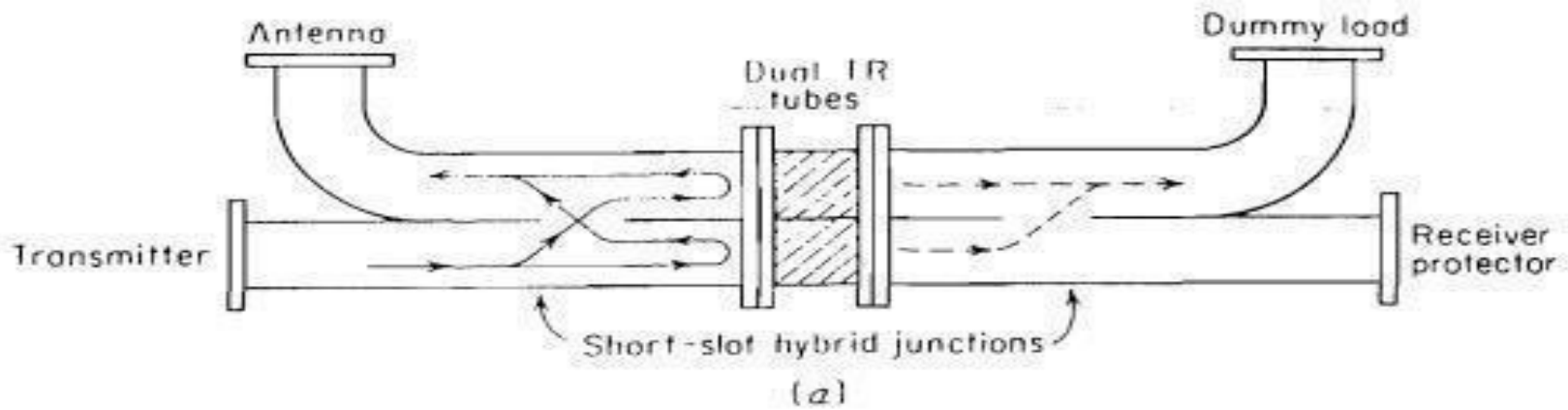
$$P_n = K T_s B G,$$

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

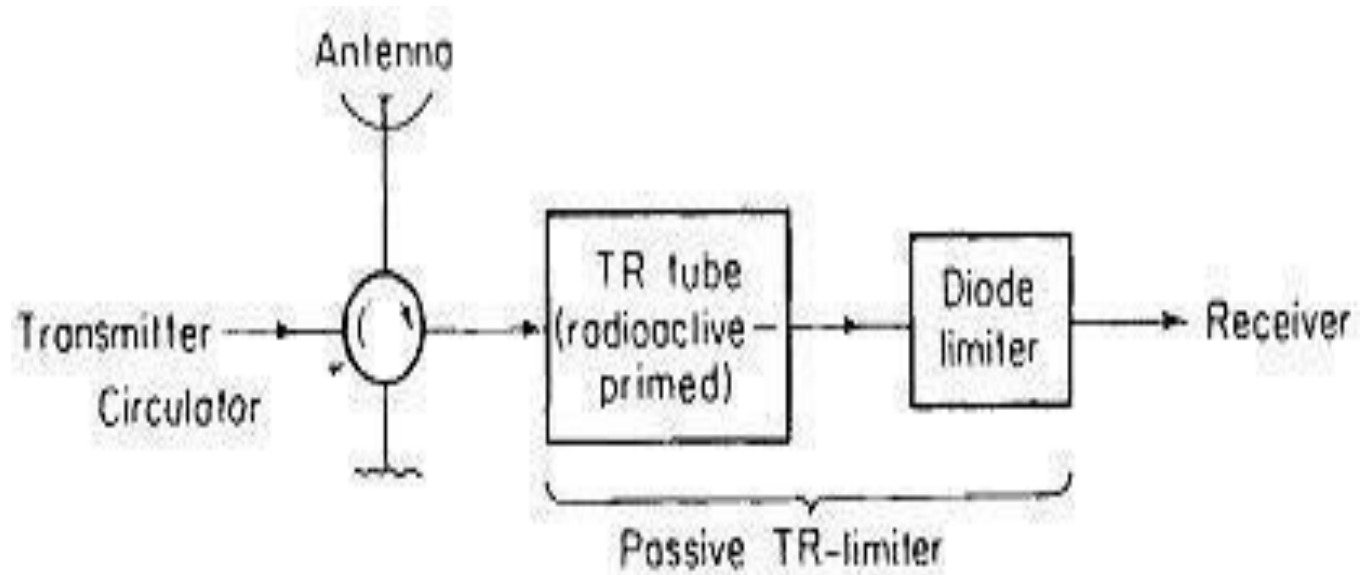
Branch-typeduplexers



Balanced duplexer



Circulator and receiver protector



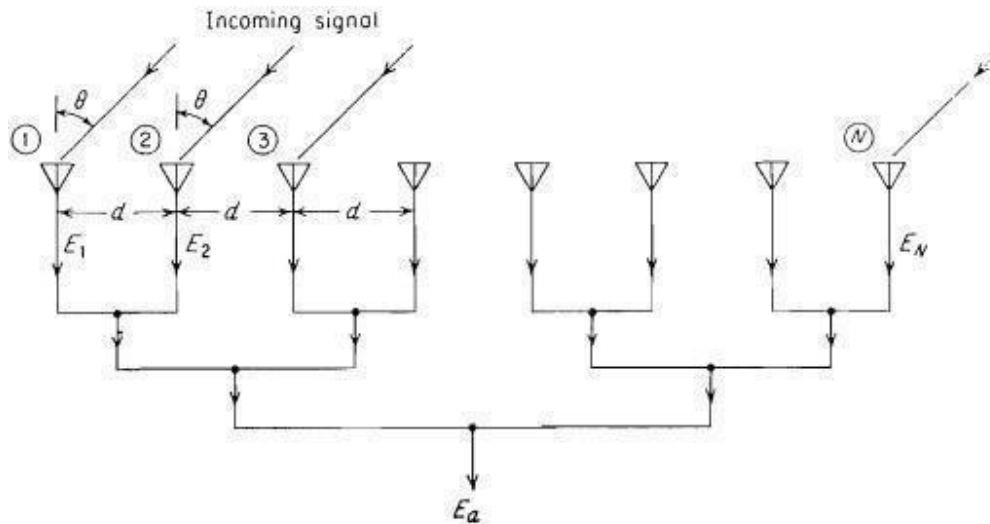
PHASED ARRAY ANTENNA

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

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

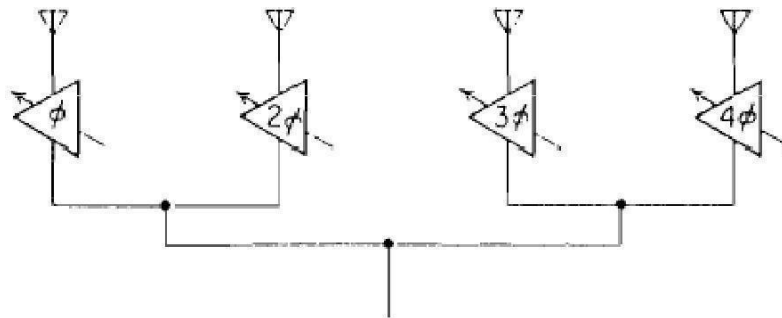


$$|E_a(\theta)| = \left| \frac{\sin [N\pi(d/\lambda) \sin \theta]}{\sin [\pi(d/\lambda) \sin \theta]} \right|$$

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

beam steering phased array antennas

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



Applications of phased array antennas

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

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.