XIV. Number Theoretic Transform (NTT)

◉ 14-A Definition

◆ **Number Theoretic Transform and Its Inverse**

$$F(k)=\sum_{n=0}^{N-1} f(n)\alpha^{nk} \pmod{M},\ k=0,1,2\cdots,N-1$$

$$f(n)=N^{-1}\sum_{k=0}^{N-1} F(k)\alpha^{-nk} \pmod{M} \quad ,n=0,1,2\cdots,N-1 \qquad f(n)\overset{NTT}{\underset{INTT}{\Longleftrightarrow}}F(k)$$

Note：

(1) M is a prime number , (mod M): 是指除以 M 的餘數

(2) N is a factor of $M-1$

(Note: when $N \neq 1$, N must be prime to M)

(3) N^{-1} is an integer that satisfies $(N^{-1})N \bmod M = 1$

(When $N = M-1$, $N^{-1} = M-1$)

(4) α is a root of unity of order N

$$\alpha^N = 1 \,(\mathrm{mod}\ M)$$

$$\alpha^k \neq 1 \,(\mathrm{mod}\ M)\ , k = 1, 2, \cdots, N-1$$

When α satisfies the above equations and $N = M - 1$, we call α the "primitive root".

$$\boxed{\begin{array}{l} \alpha^k \neq 1 \,(\mathrm{mod}\ M) \quad \text{for } k = 1, 2, \cdots, M-2 \\ \\ \alpha^{M-1} = 1 \,(\mathrm{mod}\ M) \end{array}}$$

α^{-1} 的求法與 N^{-1} 相似

α^{-1} is an integer that satisfies $\left(\alpha^{-1}\right)\alpha \bmod M = 1$

Example 1:

$M = 5 \quad \alpha = 2 \quad \alpha^1 = 2 \pmod 5 \quad \alpha^2 = 4 \pmod 5 \quad \alpha^3 = 3 \pmod 5 \quad \alpha^4 = 1 \pmod 5$

When $N = 4$

$$\begin{bmatrix} F[0] \\ F[1] \\ F[2] \\ F[3] \end{bmatrix} = \begin{bmatrix} 1 & 1 & 1 & 1 \\ 1 & 2 & 4 & 3 \\ 1 & 4 & 1 & 4 \\ 1 & 3 & 4 & 2 \end{bmatrix} \begin{bmatrix} f[0] \\ f[1] \\ f[2] \\ f[3] \end{bmatrix}$$

When $N = 2$

$$\begin{bmatrix} F[0] \\ F[1] \end{bmatrix} = \begin{bmatrix} 1 & 1 \\ 1 & 4 \end{bmatrix} \begin{bmatrix} f[0] \\ f[1] \end{bmatrix}$$

Example 2:

$M = 7$, N = 6 : α cannot be 2 but can be 3.

$\alpha = 2$: $\alpha^1 = 2 \pmod 7$ $\alpha^2 = 4 \pmod 7$ $\alpha^3 = 1 \pmod 7$

$\alpha = 3$: $\alpha^1 = 3 \pmod 7$ $\alpha^2 = 2 \pmod 7$ $\alpha^3 = 6 \pmod 7$

$\alpha^4 = 4 \pmod 7$ $\alpha^5 = 5 \pmod 7$ $\alpha^6 = 1 \pmod 7$

Advantages of the NTT:

Disadvantages of the NTT:

⦿ 14-B 餘數的計算

(1) $x \pmod M$ 的值，必定為 $0 \sim M-1$ 之間

(2) $a + b \pmod M = \{a \pmod M + b \pmod M\} \pmod M$

例： $78 + 123 \pmod 5 = 3 + 3 \pmod 5 = 1$

(Proof): If $a = a_1 M + a_2$ and $b = b_1 M + b_2$, then

$$a + b = (a_1 + b_1)M + a_2 + b_2$$

(3) $a \times b \pmod M = \{a \pmod M \times b \pmod M\} \pmod M$

例： $78 \times 123 \pmod 5 = 3 \times 3 \pmod 5 = 4$

(Proof): If $a = a_1 M + a_2$ and $b = b_1 M + b_2$, then

$$a \times b = (a_1 b_1 M + a_1 b_2 + a_2 b_1)M + a_2 b_2$$

在 Number Theory 當中

只有 M^2 個可能的加法，M^2 個可能的乘法

可事先將加法和乘法的結果存在記憶體當中

需要時再 “LUT”

LUT : lookup table

◉ 14-C Properties of Number Theoretic Transforms

P.1) Orthogonality Principle

$$S_N = \sum_{n=0}^{N-1} \alpha^{nk} \alpha^{-n\ell} = \sum_{n=0}^{N-1} \alpha^{n(k-\ell)} = N \cdot \delta_{k.\ell}$$

proof ： for $k=\ell$, $\quad S_N = \sum_{n=0}^{N-1} \alpha^0 = N$

for $k \neq 0$, $\quad (\alpha^{k-\ell l} - 1)\, S_N = (\alpha^{k-\ell} - 1) \sum_{n=0}^{N-1} \alpha^{n(k-\ell)} = \alpha^{N(k-\ell)} - 1 = 1 - 1 = 0$

$$\because \alpha^{k-\ell} \neq 1 \qquad \therefore S_N = 0$$

P.2) The NTT and INTT are exact inverse

proof ：

$$g(n) = \frac{1}{N} \sum_{k=0}^{N-1} F(k)\, \alpha^{-nk} = \frac{1}{N} \sum_{k=0}^{N-1} \left(\sum_{\ell=0}^{N-1} f(\ell)\, \alpha^{\ell k} \right) \alpha^{-nk}$$

$$= \frac{1}{N} \sum_{\ell=0}^{N-1} f(\ell) \sum_{k=0}^{N-1} \alpha^{(\ell-n)k} = \frac{1}{N} \sum_{\ell=0}^{N-1} f(\ell) \cdot N \delta_{\ell,n} = f(n)$$

P.3) Symmetry

$$f(n) = f(N-n) \quad \overset{\text{NTT}}{\Longleftrightarrow} \quad F(k) = F(N-k)$$

$$f(n) = -f(N-n) \quad \overset{\text{NTT}}{\Longleftrightarrow} \quad F(k) = -F(N-k)$$

P.4) INNT from NTT

$$f(n) = \frac{1}{N}\sum_{k=0}^{N-1} F(k)\,\alpha^{-nk} = \frac{1}{N}\sum_{(-k)=0}^{N-1} F(-k)\,\alpha^{nk} = NTT\ of\ \frac{1}{N}F(-k)$$

Algorithm for calculating the INNT from the NTT

(1) $F(-k)$: time reverse

$$F_0, F_1, F_2, \ldots, F_{N\text{-}1} \xrightarrow[\text{reverse}]{\text{time}} F_0, F_{N\text{-}1}, \ldots, F_2, F_1$$

(2) NTT[$F(-k)$]

(3) 乘上 $\frac{1}{N} = M - 1$

P.5) Shift Theorem

$$f(n+\ell) \leftrightarrow F(k)\,\alpha^{-\ell k}$$

$$f(n)\,\alpha^{n\ell} \leftrightarrow F(k+\ell)$$

P.6) Circular Convolution (the same as that of the DFT)

If $f(n) \leftrightarrow F(k)$

$g(n) \leftrightarrow G(k)$

then $f(n) \otimes g(n) \leftrightarrow F(k)G(k)$

i.e., $f(n) \otimes g(n) = INTT\{NTT[f(n)]\,NTT[g(n)]\}$

$$f(n)\cdot g(n) \leftrightarrow \frac{1}{N} F(k) \otimes G(k)$$

P.7) Parseval's Theorem

$$N\sum_{n=0}^{N-1} f(n)\, f(-n) = \sum_{k=0}^{N-1} F^2(k)$$

$$N\sum_{n=0}^{N-1} f(n)^2 = \sum_{k=0}^{N-1} F(k)F(-k)$$

P.8) Linearity

$$a\ f(n) + b\ g(n) \leftrightarrow a\ F(k) + b\ G(k)$$

P.9) Reflection

If $\quad f(n) \leftrightarrow F(k) \quad$ then $\quad f(-n) \leftrightarrow F(-k)$

◉ 14-D Efficient FFT-Like Structures for Calculating NTTs

- If N (transform length) is a power of 2, then the radix-2 FFT butterfly algorithm can be used for efficient calculation for NTT.

  Decimation-in-time NTT

  Decimation-in-frequency NTT

- The prime factor algorithm can also be applied for NTTs.

$$F(k)=\sum_{n=0}^{N-1} f(n)\,\alpha^{nk}=\sum_{r=0}^{\frac{N}{2}-1} f(2r)\,\alpha^{2rk}+\sum_{r=0}^{\frac{N}{2}-1} f(2r+1)\,\alpha^{(2r+1)k}$$

$$=\sum_{r=0}^{\frac{N}{2}-1} f(2r)\,(\alpha^{2})^{rk}+\alpha^{k}\sum_{r=0}^{\frac{N}{2}-1} f(2r+1)\,(\alpha^{2})^{rk}$$

$$=\begin{cases} G(k)+\alpha^{k}\,H(k) & ,0\le k\le \frac{N}{2}-1 \\ G(k-\frac{N}{2})+\alpha^{k}\,H(k-\frac{N}{2}) & ,\frac{N}{2}\le k\le N \end{cases}$$

where $G(k)=\sum_{r=0}^{N/2-1} f(2r)\,(\alpha^{2})^{rk}$ $\quad H(k)=\sum_{r=0}^{N/2-1} f(2r+1)\,(\alpha^{2})^{rk}$

One N-point NTT $\longrightarrow$ Two (N/2)-point NTTs

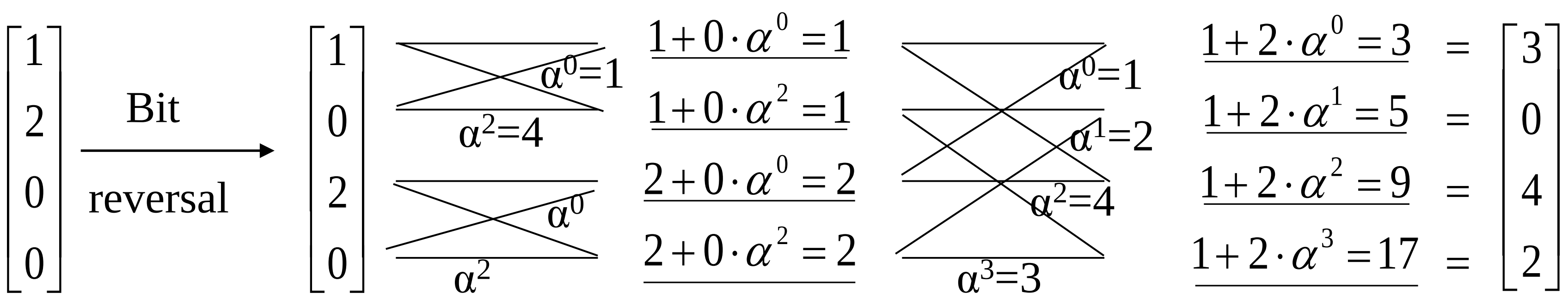
plus twiddle factors

Original sequence $f(n) = (1, 2, 0, 0)$ $N = 4, M = 5$

Permutation $(1, 0, 2, 0)$

After the 1st stage $(1, 1, 2, 2)$

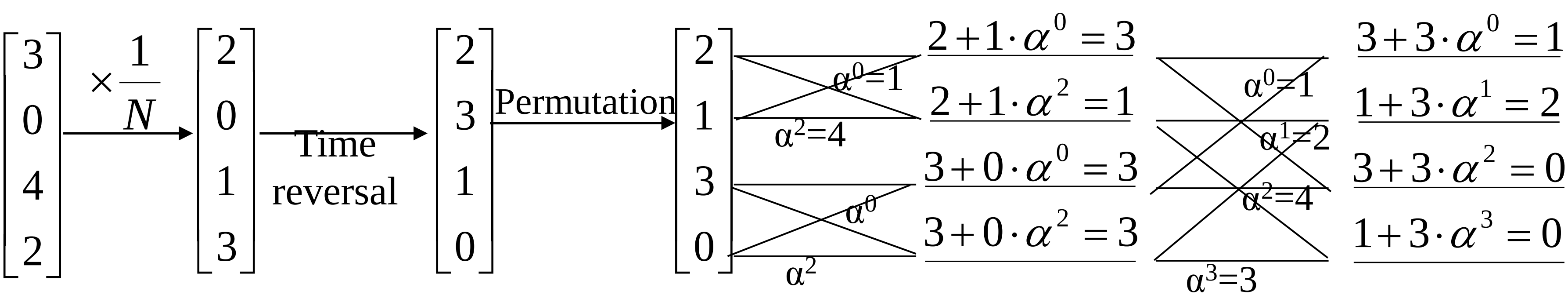
After the 2nd stage $F(k) = (3, 0, 4, 2)$



Inverse NTT by Forward NTT :

$$F(-k)\times\frac{1}{N} \qquad (4^{-1}=4)$$

1) $1/N$
2) Time reversal
3) permutation
4) After first stage
5) After 2^{nd} stage



◉ 14-E Convolution by NTT

假設 $x[n] = 0$ for $n < 0$ and $n \geq K$, $h[n] = 0$ for $n < 0$ and $n \geq H$

要計算 $x[n] * h[n] = z[n]$

且 $z[n]$ 的值可能的範圍是 $0 \leq z[n] < A$ (more general, $A_1 \leq z[n] < A_1 + T$)

(1) 選擇 M (the prime number for the modulus operator), 滿足

(a) M is a prime number, (b) $M \geq \max(H+K, A)$

(2) 選擇 N (NTT 的點數), 滿足

(a) N is a factor of $M-1$, (b) $N \geq H+K-1$

(3) 添 0: $x_1[n] = x[n]$ for $n = 0, 1, \ldots\ldots, K-1$,
$x_1[n] = 0$ for $n = K, K+1, \ldots\ldots., N-1$

$h_1[n] = h[n]$ for $n = 0, 1, \ldots\ldots, H-1$,
$h_1[n] = 0$ for $n = H, H+1, \ldots\ldots., N-1$

(4) $X_1[m] = \mathrm{NTT}_{N,M}\{x_1[n]\}$, $H_1[m] = \mathrm{NTT}_{N,M}\{h_1[n]\}$

$\mathrm{NTT}_{N,M}$ 指 N-point 的 DFT (mod M)

(5) $Z_1[m] = X_1[m]H_1[m]$, $z_1[n] = \mathrm{INTT}_{N,M}\{Z_1[m]\}$,

(6) $z[n] = z_1[n]$ for $n = 0, 1, \ldots, H+K-1$

(移去 $n = H+K, H+K+1, \ldots\ldots N-1$ 的點)

(More general, if we have estimated the range of $z[n]$ should be $A_1 \le z[n] < A_1 + T$, then

$z[n] = ((z_1[n] - A_1))_M + A_1$

適用於 (1) $x[n]$，$h[n]$皆為整數

(2) $\mathrm{Max}(z[n]) - \min(z[n]) < M$ 的情形。

Consider the convolution of (1, 2, 3, 0) * (1, 2, 3, 4)

Choose $M = 17$, $N = 8$，結果為：

• $\mathrm{Max}(z[n]) - \min(z[n])$ 的估測方法

假設 $x_1 \le x[n] \le x_2$, $\quad z[n] = x[n] * h[n] = \sum_{m=0}^{H-1} h[m]x[n-m]$

則 $\quad Max\left(z[n]\right) - \min\left(z[n]\right) = \left(x_2 + x_1\right)\sum_{n=0}^{H-1}\left|h[n]\right|$

(Proof): $\quad Max\left(z[n]\right) = \sum_{m=0}^{H-1} h_1[m]x_2 + \sum_{m=0}^{H-1} h_2[m]x_1$

where $h_1[m] = h[m]$ when $h[m] > 0$, $\quad h_1[m] = 0$ otherwise

$h_2[m] = h[m]$ when $h[m] < 0$, $\quad h_2[m] = 0$ otherwise

$$\min\left(z[n]\right) = \sum_{m=0}^{H-1} h_1[m]x_1 + \sum_{m=0}^{H-1} h_2[m]x_2$$

$$Max\left(z[n]\right) - \min\left(z[n]\right) = \sum_{m=0}^{H-1} h_1[m](x_2 - x_1) + \sum_{m=0}^{H-1} h_2[m](x_1 - x_2)$$

$$= (x_2 - x_1)\left\{\sum_{m=0}^{H-1} h_1[m] - \sum_{m=0}^{H-1} h_2[m]\right\} = (x_2 - x_1)\sum_{m=0}^{H-1}\left|h[m]\right|$$

⦿ 14-F Special Numbers

Fermat Number : $M = 2^{2^p} + 1$

$P = 0, 1, 2, 3, 4, 5, \ldots..$

$M = 3, 5, 17, 257, 65537, \ldots$

Mersenne Number : $M = 2^p + 1$

$P = 1, 2, 3, 5, 7, 13, 17, 19$

$M = 1, 3, 7, 31, 127, 8191, \ldots..$

If $M = 2^p - 1$ is a prime number, p must be a prime number.

However, if p is a prime number, $M = 2^p - 1$ may not be a prime number.

The modulus operations for Mersenne and Fermat prime numbers are very easy for implementation.

$2^k \pm 1$

Example: 25 mod 7

$$
\begin{array}{r}
11 \\
100a \,\big)\, \overline{11001} \\
\underline{100a} \\
1011 \\
\underline{100a} \\
12 \\
\downarrow \\
100
\end{array}
\qquad\qquad a = -1
$$

◉ 14-G Complex Number Theoretic Transform (CNT)

The integer field Z_M can be extended to complex integer field

If the following equation does not have a sol. in Z_M

$$x^2 = -1\,(\operatorname{mod} M) \quad \text{無解}$$

This means (-1) does not have a square root

When $M = 4k + 1$, there is a solution for $x^2 = -1$ (mod M).

When $M = 4k + 3$, there is no solution for $x^2 = -1$ (mod M).

For example, when $M = 13$, $8^2 = -1$ (mod 13).

$2^1 = 2$, $2^2 = 4$, $2^3 = 8$, $2^4 = 3$, $2^5 = 6$, $2^6 = 12 = -1$,

$2^7 = 11$, $2^8 = 9$, $2^9 = 5$, $2^{10} = 10$, $2^{11} = 7$, $2^{12} = 1$

When $M = 11$, there is no solution for $x^2 = -1$ (mod M).

If there is no solution for $x^2 = -1 \pmod{M}$, we can define an imaginary number i such that

$$i^2 = -1 \pmod{M}$$

Then, "i" will play a similar role over finite field Z_M such that plays over the complex field.

$$(a + i\,b) \pm (c + i\,d) = (a \pm c) + i\,(b \pm d)$$

$$\begin{aligned}(a + i\,b) \cdot (c + i\,d) &= ac + i^2 bd + i\,bc + i\,ad \\ &= (ac - bd) + i\,(bc + ad)\end{aligned}$$

◉ 14-H Applications of the NTT

NTT 適合作 convolution

但是有不少的限制

新的應用： encryption (密碼學)

CDMA

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XIV. Orthogonal Transform and Multiplexing

◉ 14-A Orthogonal and Dual Orthogonal

Any $M \times N$ discrete linear transform can be expressed as the matrix form:

$$\underbrace{\begin{bmatrix} y[0] \\ y[1] \\ y[2] \\ \vdots \\ y[M-1] \end{bmatrix}}_{\mathbf{Y}\,=} = \underbrace{\begin{bmatrix} \phi_0^*[0] & \phi_0^*[1] & \phi_0^*[2] & \cdots & \phi_0^*[N-1] \\ \phi_1^*[0] & \phi_1^*[1] & \phi_1^*[2] & \cdots & \phi_1^*[N-1] \\ \phi_2^*[0] & \phi_2^*[1] & \phi_2^*[2] & \cdots & \phi_2^*[N-1] \\ \vdots & \vdots & \vdots & \ddots & \vdots \\ \phi_{M-1}^*[0] & \phi_{M-1}^*[1] & \phi_{M-1}^*[2] & \cdots & \phi_{M-1}^*[N-1] \end{bmatrix}}_{\mathbf{A}} \underbrace{\begin{bmatrix} x[0] \\ x[1] \\ x[2] \\ \vdots \\ x[N-1] \end{bmatrix}}_{\mathbf{X}}$$

$$y[m] = \langle x[n], \phi_m[n] \rangle = \sum_{n=0}^{N-1} x[n]\phi_m^*[n]$$

inner product

Orthogonal: $\langle \phi_k[n], \phi_h[n] \rangle = \sum_{n=0}^{N-1} \phi_k[n] \phi_h^*[n] = 0$ **when $k \neq h$**

orthogonal transforms 的例子：

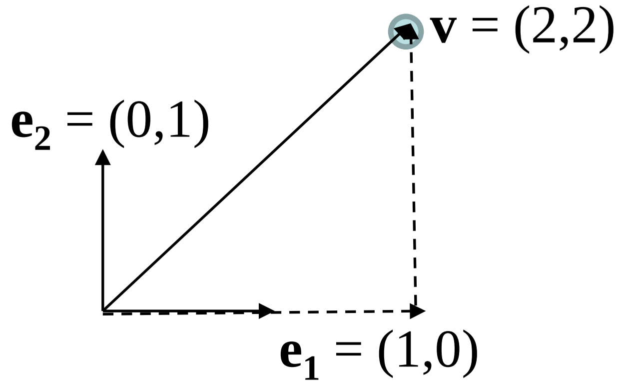
- discrete Fourier transform
- discrete cosine, sine, Hartley transforms
- Walsh Transform, Haar Transform
- discrete Legendre transform
- discrete orthogonal polynomial transforms

  Hahn, Meixner, Krawtchouk, Charlier

為什麼在信號處理上，我們經常用 orthogonal transform?

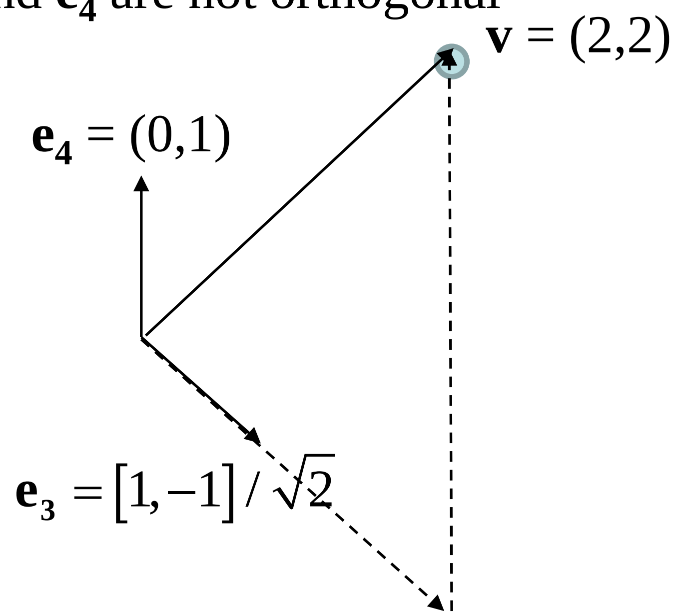
Orthogonal transform 最大的好處何在？

$\mathbf{e_1}$ and $\mathbf{e_2}$ are orthogonal



$$\mathbf{v} = 2\mathbf{e}_1 + 2\mathbf{e}_2$$

$\mathbf{e_3}$ and $\mathbf{e_4}$ are not orthogonal



$$\mathbf{v} = 2\sqrt{2}\mathbf{e}_3 + 4\mathbf{e}_4$$

- If partial terms are used for reconstruction

for orthogonal case,

perfect reconstruction: $x[n]=\sum_{m=0}^{N-1}C_m^{-1}y[m]\phi_m[n]$

partial reconstruction: $x_K[n]=\sum_{m=0}^{K-1}C_m^{-1}y[m]\phi_m[n]$ $\quad K<N$

reconstruction error of partial reconstruction

$$\left\|x[n]-x_K[n]\right\|^2=\sum_{n=0}^{N-1}\left\|\sum_{m=K}^{N-1}C_m^{-1}y[m]\phi_m[n]\right\|^2$$

$$=\sum_{n=0}^{N-1}\sum_{m=K}^{N-1}C_m^{-1}y[m]\phi_m[n]\sum_{m_1=K}^{N-1}C_{m_1}^{-1}y^*[m_1]\phi_{m_1}^*[n]$$

$$=\sum_{m=K}^{N-1}\sum_{m_1=K}^{N-1}C_m^{-1}y[m]C_{m_1}^{-1}y^*[m_1]\sum_{n=0}^{N-1}\phi_m[n]\phi_{m_1}^*[n]$$

$$=\sum_{m=K}^{N-1}\sum_{m_1=K}^{N-1}C_m^{-1}y[m]C_{m_1}^{-1}y^*[m_1]C_m\delta[m-m_1]=\sum_{m=K}^{N-1}C_m^{-1}\left|y[m]\right|^2$$

由於 $C_m^{-1}\left|y[m]\right|^2$ 一定是正的，可以保證 <u>K 越大, reconstruction error 越小</u>

For non-orthogonal case,

perfect reconstruction: $$x[n]=\sum_{m=0}^{N-1}B[n,m]y[m]$$ $\mathbf{B} = \mathbf{A}^{-1}$

partial reconstruction: $$x_K[n]=\sum_{m=0}^{K-1}B[n,m]y[m]$$ $K<N$

reconstruction error of partial reconstruction

$$\left\|x[n]-x_K[n]\right\|^2=\sum_{n=0}^{N-1}\left\|\sum_{m=K}^{N-1}B[n,m]y[m]\right\|^2$$

$$=\sum_{n=0}^{N-1}\sum_{m=K}^{N-1}B[n,m]y[m]\sum_{m_1=K}^{N-1}B^*[n,m_1]y^*[m_1]$$

$$=\sum_{m=K}^{N-1}\sum_{m_1=K}^{N-1}y[m]y^*[m_1]\sum_{n=0}^{N-1}B[n,m]B^*[n,m_1]$$

由於 $y[m]y^*[m_1]\sum_{n=0}^{N-1}B[n,m]B^*[n,m_1]$ 不一定是正的，

無法保證 K 越大, reconstruction error 越小

◎ 14-B Frequency and Time Division Multiplexing

傳統 Digital Modulation and Multiplexing：使用 Fourier transform

• Frequency-Division Multiplexing (FDM)

$$z(t) = \sum_{n=0}^{N-1} X_n \exp\left(j2\pi f_n t\right)$$

$X_n = 0$ or 1

X_n can also be set to be -1 or 1

When (1) $t \in [0, T]$ (2) $f_n = n/T$

$$z(t) = \sum_{n=0}^{N-1} X_n \exp\left(j\frac{2\pi nt}{T}\right)$$

it becomes the **orthogonal frequency-division multiplexing (OFDM).**

Furthermore, if the time-axis is also sampled

$t \in [0,T]$
sampling for t-axis

$$t = mT/N, \qquad m = 0, 1, 2, \ldots.., N-1$$

$$z\left(m\frac{T}{N}\right) = \sum_{n=0}^{N-1} X_n \exp\left(j\frac{2\pi nm}{N}\right)$$

then the OFDM is equivalent to the transform matrix of the inverse discrete Fourier transform (IDFT), which is one of the discrete orthogonal transform.

Modulation: $$Y_m = z\left(m\frac{T}{N}\right) = \sum_{m=0}^{N-1} A[m,n]X_n$$

$$\mathbf{A} = \begin{bmatrix} 1 & 1 & 1 & \cdots & 1 \\ 1 & e^{j\frac{2\pi}{N}} & e^{j\frac{4\pi}{N}} & \cdots & e^{j\frac{2(N-1)\pi}{N}} \\ 1 & e^{j\frac{4\pi}{N}} & e^{j\frac{8\pi}{N}} & \cdots & e^{j\frac{4(N-1)\pi}{N}} \\ \vdots & \vdots & \vdots & \ddots & \vdots \\ 1 & e^{j\frac{2(N-1)\pi}{N}} & e^{j\frac{4(N-1)\pi}{N}} & \cdots & e^{j\frac{2(N-1)(N-1)\pi}{N}} \end{bmatrix}$$

Modulation: $$Y_m = \sum_{m=0}^{N-1} A[m,n] X_n$$

Demodulation: $$X_n = \frac{1}{N} \sum_{m=0}^{N-1} A^*[m,n] Y_m$$

Example: $N = 8$

$X_n = [1, 0, 1, 1, 0, 0, 1, 1]$ $(n = 0 \sim 7)$

- **Time-Division Multiplexing (TDM)**

$$z(0) = X_0, \quad z\left(\frac{T}{N}\right) = X_1, \quad z\left(2\frac{T}{N}\right) = X_2, \quad \cdots\cdots, \quad z\left((N-1)\frac{T}{N}\right) = X_{N-1}$$

$$y(m) = z\left(m\frac{T}{N}\right) = \sum_{m=0}^{N-1} A[m,n] X_n$$

$$\mathbf{A} = \begin{bmatrix} 1 & 0 & 0 & \cdots & 0 \\ 0 & 1 & 0 & \cdots & 0 \\ 0 & 0 & 1 & \cdots & 0 \\ \vdots & \vdots & \vdots & \ddots & \vdots \\ 0 & 0 & 0 & \cdots & 1 \end{bmatrix}$$

(also a discrete orthogonal transform)

思考：

既然 time-division multiplexing 那麼簡單

那為什麼要使用 frequency-division multiplexing
和 orthogonal frequency-division multiplexing (OFDM)?

◉ 14-C Code Division Multiple Access (CDMA)

除了 frequency-division multiplexing 和 time-division multiplexing，是否還有其他 multiplexing 的方式？

使用其他的 orthogonal transforms
即 code division multiple access (CDMA)

CDMA is an important topic in spread spectrum communication

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[2] 邱國書, 陳立民譯, “CDMA 展頻通訊原理”, 五南, 台北, 2002.

CDMA 最常使用的 orthogonal transform 為 Walsh transform

$$\begin{bmatrix}y_1\\y_2\\y_3\\y_4\\y_5\\y_6\\y_7\\y_8\end{bmatrix}=\begin{bmatrix}1&1&1&1&1&1&1&1\\1&1&1&1&-1&-1&-1&-1\\1&1&-1&-1&-1&-1&1&1\\1&1&-1&-1&1&1&-1&-1\\1&-1&-1&1&1&-1&-1&1\\1&-1&-1&1&-1&1&1&-1\\1&-1&1&-1&-1&1&-1&1\\1&-1&1&-1&1&-1&1&-1\end{bmatrix}\begin{bmatrix}x_1\\x_2\\x_3\\x_4\\x_5\\x_6\\x_7\\x_8\end{bmatrix}\begin{array}{l}\leftarrow\text{channel 1}\\\leftarrow\text{channel 2}\\\leftarrow\text{channel 3}\\\leftarrow\text{channel 4}\\\leftarrow\text{channel 5}\\\leftarrow\text{channel 6}\\\leftarrow\text{channel 7}\\\leftarrow\text{channel 8}\end{array}$$

channel 1

當有兩組人在同一個房間裡交談 (A 和B交談)，(C 和D交談) ，
如何才能夠彼此不互相干擾？

(1) Different Time

(2) Different Tone

(3) Different Language

CDMA 分為：

(1) Orthogonal Type (2) Pseudorandom Sequence Type

Orthogonal Type 的例子： 兩組資料 [1, 0, 1] [1, 1, 0]

(1) 將 0 變為 −1 [1, −1, 1] [1, 1, −1]

(2) 1, −1, 1 modulated by [1, 1, 1, 1, 1, 1, 1, 1] (channel 1)

→ [1, 1, 1, 1, 1, 1, 1, 1, -1, -1, -1, -1, -1, -1, -1, -1, 1, 1, 1, 1, 1, 1, 1, 1]

1, 1, −1 modulated by [1, 1, 1, 1, -1, -1, -1, -1] (channel 2)

→ [1, 1, 1, 1, -1, -1, -1, -1, 1, 1, 1, 1, -1, -1, -1, -1, -1, -1, -1, -1, 1, 1, 1, 1]

(3) 相合

[2, 2, 2, 2, 0, 0, 0, 0, 0, 0, 0, 0, -2, -2, -2, -2, 0, 0, 0, 0, 2, 2, 2, 2] demodulation

[2, 2, 2, 2, 0, 0, 0, 0, 0, 0, 0, 0, -2, -2, -2, -2, 0, 0, 0, 0, 2, 2, 2, 2]

[1, 1, 1, 1, 1, 1, 1, 1]   [1, 1, 1, 1, 1, 1, 1,1]

[1, 1, 1, 1, 1, 1, 1, 1]

內積 = 8

注意：

(1) 使用 N-point Walsh transform 時，總共可以有N 個 channels

(2) 除了 Walsh transform 以外，其他的 orthogonal transform 也可以使用

(3) 使用 Walsh transform 的好處

- Orthogonal Transform 共通的問題:　需要同步 synchronization

$\mathbf{R_1}$ = [1,　1,　1,　1,　1,　1,　1,　1]

$\mathbf{R_2}$ = [1,　1,　1,　1, –1, –1, –1, –1]

$\mathbf{R_5}$ = [1, –1, –1,　1,　1, –1, –1,　1]

$\mathbf{R_8}$ = [1, –1,　1, –1,　1, –1,　1, –1]

但是某些 basis, 就算不同步也近似 orthogonal

$<\mathbf{R_1}[n], \mathbf{R_1}[n]> = 8$,　$<\mathbf{R_1}[n], \mathbf{R_k}[n]> = 0$ if $k \neq 1$

$<\mathbf{R_1}[n], \mathbf{R_k}[n-1]> = 2$ or 0　if $k \neq 1$.

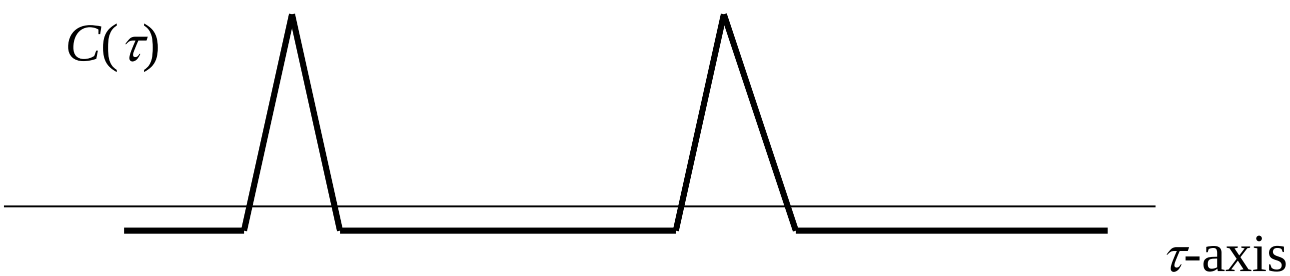
這裡的shift為circular shift

Pseudorandom Sequence Type

不為 orthogonal，capacity 較少

但是不需要同步 (asynchronous)

Pseudorandom Sequence 之間的 correlation



$b_1 p(t+\tau_1) + b_2 p(t+\tau_2)$

recovered: $\int \left(b_1 p(t+\tau_1) + b_2 p(t+\tau_2)\right) p(t+\tau_1)\,dt = b_1 C\left(0\right) + b_2 C\left(\tau_2 - \tau_1\right) \approx b_1$

(若 $C(0) = 1$, $C(\tau_2 - \tau_1) \approx 0$)

τ_1, τ_2 不必一致

CDMA 的優點：

(1) 運算量相對於 frequency division multiplexing 減少很多

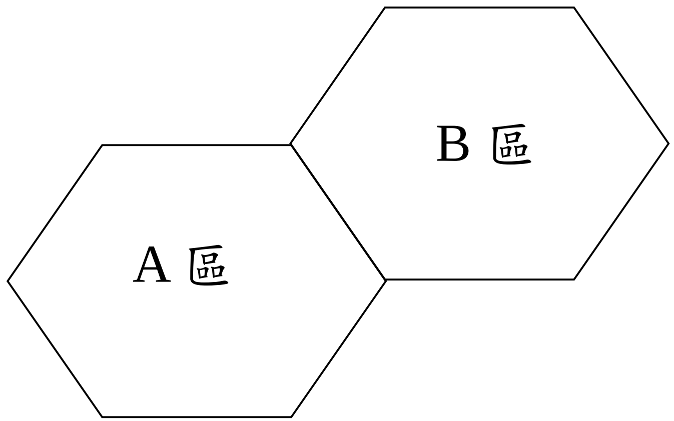
(2) 可以減少 noise 及 interference的影響

(3) 可以應用在保密和安全傳輸上

(4) 就算只接收部分的信號，也有可能把原來的信號 recover 回來

(5) 相鄰的區域的干擾問題可以減少

相鄰的區域，使用差距最大的「語言」，則干擾最少



假設 A 區使用的 orthogonal basis 為 $\phi_k[n]$, $k = 0, 1, 2, \ldots, N-1$

B 區使用的 orthogonal basis 為 $\mu_h[n]$, $h = 0, 1, 2, \ldots, N-1$

設法使 $\max\left(\left|\dfrac{\langle \phi_k[n], \mu_h[n] \rangle}{\langle \phi_k[n], \phi_h[n] \rangle}\right|\right)$ 為最小

$k = 0, 1, 2, \ldots, N-1$, $h = 0, 1, 2, \ldots, N-1$

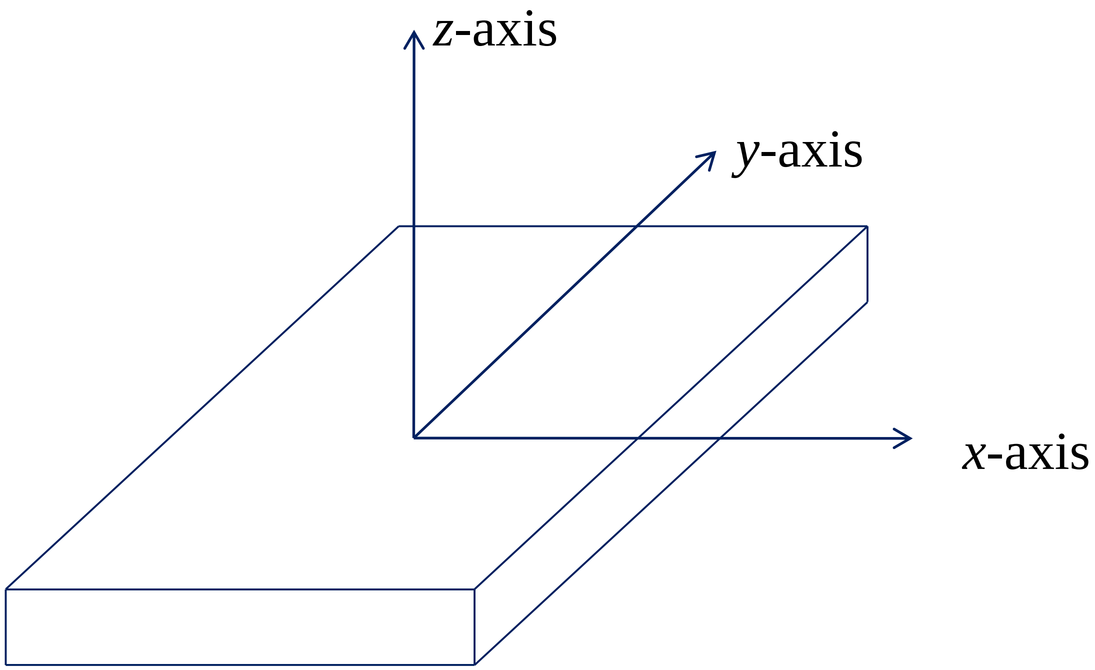
附錄十四 3-D Accelerometer 的簡介

3-D Accelerometer: 三軸加速器，或稱作加速規

許多儀器(甚至包括智慧型手機) 都有配置三軸加速器

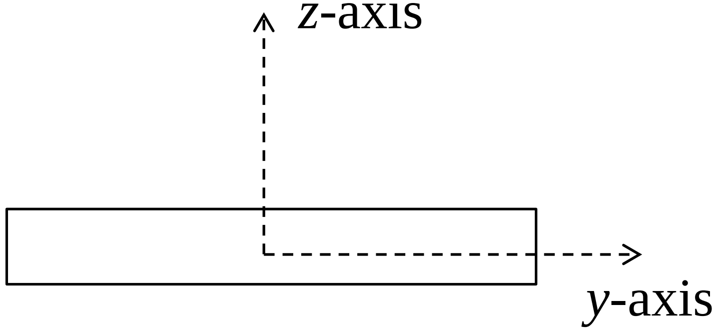
可以用來判別一個人的姿勢和動作

註：Gyrator (陀螺儀) 可以用來量測物體旋轉之方向，可補 3-D Accelerometer 之不足，許多儀器 (包括智慧型手機) 也內建陀螺儀之裝置， 3-D Accelerometer Signal Processing 和 gyrator signal processing 經常並用



根據 x, y, z 三個軸的加速度的變化，來判斷姿勢和動作

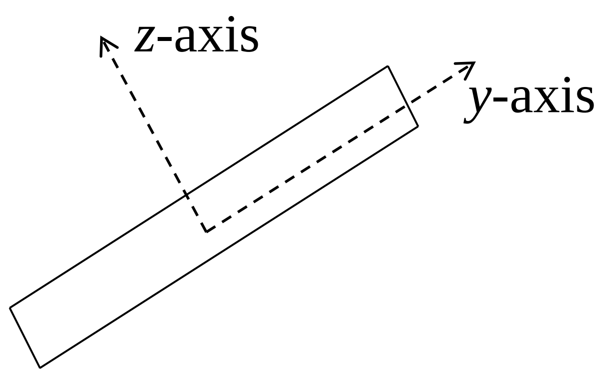
平放且靜止時， z-axis 的加速度為 $-g = -9.8$



y: 0

z: -9.8

tilted by θ



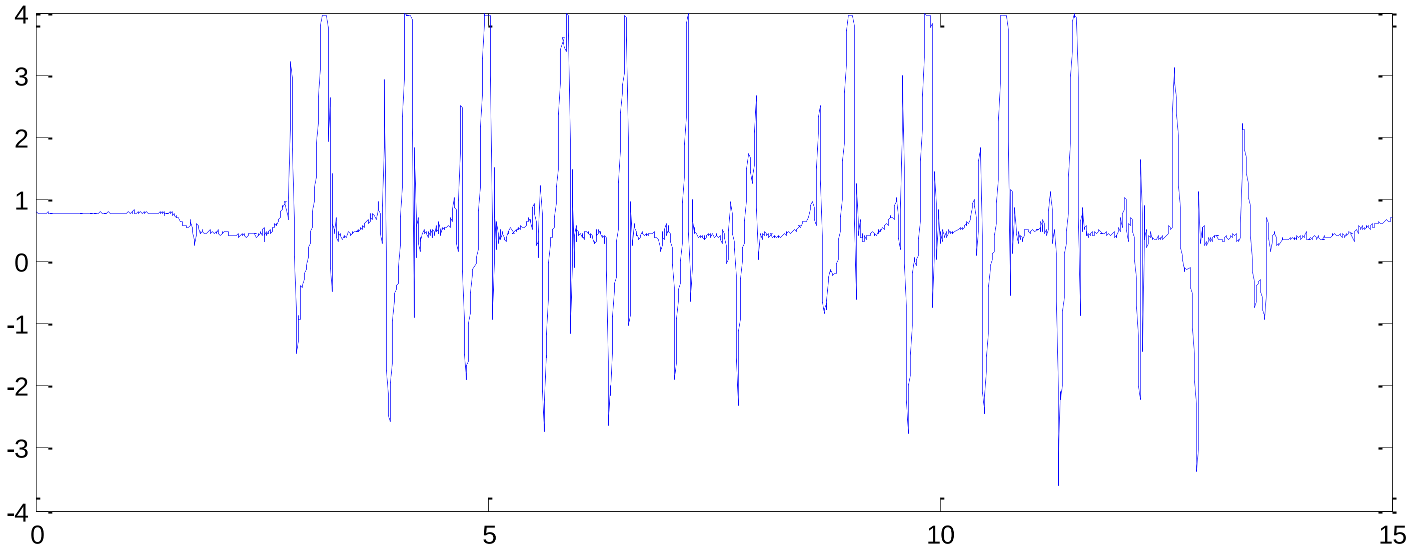
y: -9.8sin θ

z: -9.8cos θ

可藉由加速規傾斜的角度，來判斷姿勢和動作

例子：若將加速規放在腳上................

走路時，沿著其中一個軸的加速度變化



應用： 動作辨別 (遊戲機)

運動 (訓練，計步器)

醫療復健，如 Parkinson 患者照顧，傷患復原情形

其他 (如動物的動作，機器的運轉情形的偵測)

3-D Accelerometer Signal Processing 是訊號處理的重要課題之一

一方面固然是因為應用多，另一方面， 3-D Accelerometer Signal 容易受 noise 之干擾，要如何藉由 3-D Accelerometer Signal 來還原動作以及移動速度，仍是個挑戰

祝各位同學暑假愉快！

各位同學在研究上或工作上，有任何和 digital signal processing 或 time frequency analysis 方面的問題，歡迎找我來一起討論。