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## CORDIC: Cartesian to Polar Coordinate Transformation

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# 1 Introduction

## 1.1 Specification

It is required to design a digital circuit for implementing the transformation from cartesian coordinates into polar coordinates using the CORDIC algorithm in Vectoring mode. It is implemented with these recursive equations:

$$\begin{aligned}x_{i+1} &= x_i - y_i \cdot d_i \cdot 2^{-i} \\y_{i+1} &= y_i + x_i \cdot d_i \cdot 2^{-i} \\z_{i+1} &= z_i - d_i \cdot \arctan(2^{-i})\end{aligned}$$

where  $d_i = -1$  if  $y_i > 0$ ,  $+1$  otherwise. After  $n$  iterations, the equations converge to:

$$\begin{aligned}x_n &= A_n \cdot \sqrt{x_0^2 + y_0^2} \\y_n &= 0 \\z_n &= z_0 + \arctan\left(\frac{y_0}{x_0}\right) \\A_n &= \prod_{i=0}^n \sqrt{1 + 2^{-2i}}\end{aligned}$$

## 1.2 Circuit Applications

The CORDIC (COordinate Rotation DIgital Computer) algorithm is an iterative method for performing vector rotations and solving mathematical functions such as trigonometric, hyperbolic, exponential, logarithmic, and square root operations. It was introduced by Jack E. Volder in 1959 to simplify the computation of these functions in hardware with limited resources.

CORDIC is widely used because it eliminates the need for multiplication and division, relying instead on shift and addition operations. This makes it highly efficient for

hardware implementations, particularly in devices with limited computational power, such as embedded systems, calculators, and digital signal processors (DSPs).

For example the Intel 8087, a floating-point coprocessor introduced in the early 1980s, utilized the CORDIC algorithm to perform efficient trigonometric and hyperbolic computations, such as sine, cosine, and arctangent, without relying on hardware multipliers. Similarly, during the Apollo Lunar Module missions, a precursor concept to CORDIC was employed in the Apollo Guidance Computer (AGC) to perform real-time navigation calculations. The AGC used iterative methods to determine angles and distances for lunar landings, efficiently converting Cartesian spacecraft coordinates to polar forms to ensure precise trajectory adjustments during descent.

The CORDIC algorithm can operate in two different modes: **rotation mode** and **vectoring mode**

- **Rotation mode:** rotates a vector by a specified angle, used for calculating trigonometric functions or vector transformations
- **Vectoring mode:** determines the magnitude and angle of a vector, useful for converting Cartesian to polar coordinates

In this context, this project will focus on developing the vectoring mode of the CORDIC algorithm to convert Cartesian coordinates into polar form.

## 2 Architecture

By default, the CORDIC algorithm converges only for input angles within the range  $(-99.7^\circ, 99.7^\circ)$ . To address this limitation and enable the algorithm to handle arbitrary input angles, we introduced an **initial correction step**. This step adjusts the input angle to bring it into the principal range of the algorithm. The adjustment ensures that the CORDIC algorithm works seamlessly for all input angles, not just those within the default convergence range.

$$x_0 = -y_{\text{input}} \cdot d_{\text{input}}$$

$$y_0 = x_{\text{input}} \cdot d_{\text{input}}$$

$$z_0 = -\frac{\pi}{2} \cdot d_{\text{input}}$$

Additionally, since the iterative process of the CORDIC algorithm introduces a scaling factor  $A_n$ , we normalize the final result by dividing  $\rho$  (the magnitude) by  $A_n$ .

### 2.1 Data Representation

To implement the CORDIC algorithm, we used fixed-point arithmetic for the input and intermediate values. Specifically:

- $x, y$  : signed 16-bit fixed-point representation with 8 bits allocated for the fractional part.
- $\rho$  : unsigned 16-bit fixed-point representation with 8 bits allocated for the fractional part.
- $z, \theta$  : signed 16-bit fixed-point representation with 13 bits allocated for the fractional part. This decision was made because they always lie within the range  $[-\pi, \pi]$ , and the additional fractional bits ensure high angular precision.
- For the intermediate calculations a 24-bit representation was used to minimize truncation errors during the iterative process.
- All the inputs and the outputs are limited to 16 bits due to the I/O pin constraints of the Zybo board.

The number of iterations for the CORDIC algorithm was set to 16, as this provides a high level of precision while balancing computational efficiency. Beyond 16 iterations, the precision gained decreases significantly.

## 2.2 Module Precision

Focusing on the module,  $\rho$  is unsigned so that outputs with  $\rho \geq 128$  can be represented. For the intermediate calculation the representation has 2 more bits for the integer part, this ensures that there isn't an overflow on  $x$  during the calculations.

## 2.3 Phase Precision and Error Analysis

Focusing on the phase, the intermediate values are represented in Q3.21 fixed-point format, offering a maximum absolute error  $\epsilon_a$  of  $2^{-21}$ . Over the course of 16 iterations, the maximum accumulated absolute sum of these values  $\epsilon_M$  is

$$\epsilon_M = \epsilon_a * 16 = 2^{-21} * 2^4 = 2^{-17}$$

Since the final result is truncated to Q3.13, which involves discarding the least significant bits (LSBs), the accumulated error from the iterative sums becomes negligible. This ensures that the phase computation maintains high precision.

# 3 VHDL code

## 3.1 CORDIC

The following code shows the implementation of the CORDIC in vectoring mode for cartesian to polar conversion. This implementation supports the fix step for accepting inputs in all 4 quadrants, and also normalizes  $\rho$ .

```
1 LIBRARY ieee;
2 USE ieee.std_logic_1164.ALL;
3 USE ieee.numeric_std.ALL;
4 ENTITY CORDIC IS
5
6   GENERIC (
7     M : POSITIVE := 24; -- internal representation size
8     N : POSITIVE := 16; -- input size
9     ITERATIONS : POSITIVE := 16; -- CORDIC algorithm iterations
10    ITER_BITS : POSITIVE := 4 -- number of bits needed to represent
11      → iterations
12  );
13  PORT (
14    clk : IN STD_LOGIC;
15    rst : IN STD_LOGIC;
16    x : IN STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
17    y : IN STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
18    start : IN STD_LOGIC;
19    rho : OUT STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
20    theta : OUT STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
21    valid : OUT STD_LOGIC
22  );
23
24 END ENTITY;
25
26 ARCHITECTURE behavioral OF CORDIC IS
27
28   CONSTANT k : UNSIGNED(M - 1 DOWNTO 0) :=
29     → to_unsigned(INTEGER(0.6072528458 * (2 ** (M - 1))), M);
30   CONSTANT HALF_PI : SIGNED(M - 1 DOWNTO 0) :=
31     → to_signed(INTEGER(1.570796327 * (2 ** (M - 3))), M);
32
33   -- internal registers
```

```

31  SIGNAL x_t : SIGNED(M - 1 DOWNTO 0);
32  SIGNAL y_t : SIGNED(M - 1 DOWNTO 0);
33  SIGNAL z_t : SIGNED(M - 1 DOWNTO 0);
34
35  -- output registers
36  SIGNAL x_out : STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
37  SIGNAL z_out : STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
38
39  -- atan table address and output
40  SIGNAL address : STD_LOGIC_VECTOR(ITER_BITS - 1 DOWNTO 0);
41  SIGNAL atan_out : STD_LOGIC_VECTOR(M - 1 DOWNTO 0);
42
43  SIGNAL sign : STD_LOGIC;
44
45  -- atan table
46  COMPONENT ATAN_LUT IS
47    PORT (
48      address : IN STD_LOGIC_VECTOR(ITER_BITS - 1 DOWNTO 0);
49      lut_out : OUT STD_LOGIC_VECTOR(M - 1 DOWNTO 0)
50    );
51  END COMPONENT;
52
53  -- state type and registers
54  TYPE state_t IS (WAITING, FIX, COMPUTING, FINISHED);
55  SIGNAL current_state : state_t;
56
57  -- counter for iterations
58  SIGNAL counter : UNSIGNED(ITER_BITS - 1 DOWNTO 0);
59
60 BEGIN
61  -----
62  -- INSTANTIATE ALL COMPONENTS
63  -----
64
65  -- output assignment
66  rho <= x_out;
67  theta <= z_out;
68
69  -- sign bit
70  sign <= y_t(M - 1);
71
72  -- atan table
73  atan_lut_inst : ATAN_LUT
74  PORT MAP(
75    address => address,
76    lut_out => atan_out
77  );
78
79  -- atan table address
80  address <= STD_LOGIC_VECTOR(counter);
81
82  -----
83  -- CONTROL PART

```

```

84 -----
85
86 control : PROCESS (clk, rst)
87 BEGIN
88   IF (rising_edge(clk)) THEN
89     IF rst = '1' THEN
90       current_state <= WAITING;
91     ELSE
92
93     CASE current_state IS
94       WHEN WAITING =>
95         IF start = '1' THEN
96           current_state <= FIX;
97         ELSE
98           current_state <= WAITING;
99         END IF;
100
101      WHEN FIX =>
102        current_state <= COMPUTING;
103
104      WHEN COMPUTING =>
105        IF counter = ITERATIONS - 1 THEN
106          current_state <= FINISHED;
107        ELSE
108          current_state <= COMPUTING;
109        END IF;
110
111      WHEN FINISHED =>
112        current_state <= WAITING;
113
114      WHEN OTHERS =>
115        current_state <= WAITING;
116
117    END CASE;
118  END IF;
119 END IF;
120 END PROCESS;
121
122 -----
123 -- OPERATIONAL PART
124 -----
125
126 OPEATIONAL : PROCESS (clk, rst)
127 BEGIN
128   IF (rising_edge(clk)) THEN
129     IF rst = '1' THEN
130       valid <= '0';
131       x_out <= (OTHERS => '0');
132       z_out <= (OTHERS => '0');
133       counter <= (OTHERS => '0');
134       x_t <= (OTHERS => '0');
135       y_t <= (OTHERS => '0');
136       z_t <= (OTHERS => '0');

```

```

137      ELSE
138
139          -- Default assignment
140          x_t <= (OTHERS => '-');
141          y_t <= (OTHERS => '-');
142          z_t <= (OTHERS => '-');
143          x_out <= (OTHERS => '-');
144          z_out <= (OTHERS => '-');
145          counter <= (OTHERS => '0');
146
147      CASE current_state IS
148          WHEN WAITING =>
149              -- x_t and y_t have 2 more bits for the integer compared to
150              -- x and y
151              -- this avoids overflows during the computation
152              x_t <= shift_left(resize(signed(x), M), (M - N - 2));
153              y_t <= shift_left(resize(signed(y), M), (M - N - 2));
154              z_t <= to_signed(0, M);
155              valid <= '1';
156              x_out <= x_out;
157              z_out <= z_out;
158
159          WHEN FIX =>
160              IF sign = '1' THEN
161                  x_t <= - y_t;
162                  y_t <= x_t;
163                  z_t <= z_t - HALF_PI;
164              ELSE
165                  x_t <= y_t;
166                  y_t <= - x_t;
167                  z_t <= z_t + HALF_PI;
168              END IF;
169
170              valid <= '0';
171              counter <= (OTHERS => '0');
172
173          WHEN COMPUTING =>
174              IF sign = '1' THEN
175                  x_t <= x_t - shift_right(y_t, to_integer(counter));
176                  y_t <= y_t + shift_right(x_t, to_integer(counter));
177                  z_t <= z_t - signed(atan_out);
178              ELSE
179                  x_t <= x_t + shift_right(y_t, to_integer(counter));
180                  y_t <= y_t - shift_right(x_t, to_integer(counter));
181                  z_t <= z_t + signed(atan_out);
182              END IF;
183
184              counter <= counter + 1;
185
186              valid <= '0';
187
188          WHEN FINISHED =>

```

```

188      x_out <= STD_LOGIC_VECTOR(resize(shift_right(unsigned(x_t) *
189        => k, M - 1), M)(M - 1 - 2 DOWNTO M - N - 2));
190      z_out <= STD_LOGIC_VECTOR(z_t(M - 1 DOWNTO M - N));
191
192      valid <= '1';
193
194      END CASE;
195      END IF;
196      END IF;
197      END PROCESS;
END ARCHITECTURE;

```

Listing 3.1: CORDIC.vhd

## 3.2 Atan LUT

The values of the LUT table were calculated using the formula:

$$\text{LUT}_i = \lfloor \text{atan}(2^{-i}) * 2^{21} \rfloor$$

```

1 library IEEE;
2 use IEEE.std_logic_1164.all;
3 use IEEE.numeric_std.all;
4
5 ENTITY ATAN_LUT IS
6   port (
7     address : in std_logic_vector(3 downto 0);
8     lut_out : out std_logic_vector(23 downto 0)
9   );
10 end entity;
11
12 architecture rtl of ATAN_LUT is
13
14   type LUT_t is array (natural range 0 to 15) of integer;
15   constant LUT: LUT_t := (
16     0 => 1647099,
17     1 => 972339,
18     2 => 513757,
19     3 => 260791,
20     4 => 130901,
21     5 => 65514,
22     6 => 32765,
23     7 => 16383,
24     8 => 8191,
25     9 => 4095,
26     10 => 2047,

```

```
27      11 => 1023,
28      12 => 511,
29      13 => 255,
30      14 => 127,
31      15 => 63
32    );
33
34 begin
35
36 PROCESS (address)
37 BEGIN
38   lut_out <=
39     STD_LOGIC_VECTOR(to_signed(LUT(to_integer(unsigned(address))), 
40                           24));
41 END PROCESS;
42
43 end architecture;
```

Listing 3.2: ATAN\_LUT.vhd

# 4 Verification and testing

## 4.1 Testbench

The testbench CORDIC\_tb verifies the basic functionality of the circuit by performing a power on reset and iteratively gives one input and waits for the corresponding output. For debugging reasons the testbench also prints the output values on the console.

```
1 LIBRARY IEEE;
2 USE IEEE.STD_LOGIC_1164.ALL;
3 USE IEEE.NUMERIC_STD.ALL;
4 USE ieee.math_real.ALL;
5
6 ENTITY CORDIC_TB IS
7   GENERIC (
8     N : POSITIVE := 16;
9     floating : INTEGER := 8
10    );
11 END CORDIC_TB;
12
13 ARCHITECTURE Behavioral OF CORDIC_TB IS
14   -- Component declaration for CORDIC
15
16   COMPONENT CORDIC
17     PORT (
18       clk : IN STD_LOGIC;
19       rst : IN STD_LOGIC;
20       x : IN STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
21       y : IN STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
22       start : IN STD_LOGIC;
23       rho : OUT STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
24       theta : OUT STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
25       valid : OUT STD_LOGIC
26     );
27   END COMPONENT;
28
29   -- Signals for CORDIC inputs and outputs
30
31   SIGNAL clk : STD_LOGIC := '0';
32   SIGNAL reset : STD_LOGIC := '0';
```

```

33  SIGNAL x : STD_LOGIC_VECTOR(N - 1 DOWNTO 0) := (OTHERS => '0');
34  SIGNAL y : STD_LOGIC_VECTOR(N - 1 DOWNTO 0) := (OTHERS => '0');
35  SIGNAL start : STD_LOGIC := '0';
36  SIGNAL rho : STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
37  SIGNAL theta : STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
38  SIGNAL valid : STD_LOGIC := '0';
39
40  SIGNAL run_simulation : STD_LOGIC := '1';
41
42  -- Clock period definition
43  CONSTANT T_clk : TIME := 20 ns;
44
45  -- Coordinate type
46  TYPE Coordinate IS RECORD
47    x : real;
48    y : real;
49  END RECORD;
50  CONSTANT n_coordinates : NATURAL := 9;
51
52  TYPE CoordinateArray IS ARRAY (0 TO n_coordinates - 1) OF Coordinate;
53
54  -- Array of coordinates to test
55  CONSTANT Coordinates : CoordinateArray := (
56
56    (1.0, 1.0),
57    (10.0, 10.0),
58    (0.0, 1.0),
59    (-0.1, -4.0),
60    (-1.0, 1.0),
61    (-1.0, 0.0),
62    (-1.0, 0.1),
63    (31.0, 31.0),
64    (127.0, 127.0)
65  );
66
67  -- function to print values in report
68  FUNCTION to_real(val : unsigned(N - 1 DOWNTO 0); fraction_bits :
69    → INTEGER) RETURN real IS
70  BEGIN
71    RETURN real(to_integer(val)) / 2.0 ** fraction_bits;
72  END FUNCTION;
73
74  -- function to print values in report
75  FUNCTION to_real(val : signed(N - 1 DOWNTO 0); fraction_bits :
76    → INTEGER) RETURN real IS
77  BEGIN
78    RETURN real(to_integer(val)) / 2.0 ** fraction_bits;
79  END FUNCTION;
80
81  PROCEDURE echo(arg : IN STRING := "") IS
82  BEGIN
83    std.textio.write(std.textio.output, arg & LF); -- LF ensures a
84    → newline after each message

```

```

83      END PROCEDURE echo;
84
85  BEGIN
86    -- Instantiate the CORDIC component
87    cordic_inst : CORDIC
88    PORT MAP(
89      clk => clk,
90      rst => reset,
91      x => x,
92      y => y,
93      start => start,
94      rho => rho,
95      theta => theta,
96      valid => valid
97    );
98
99    -- todo fix behavior if cordic is not ready / does not work
100   clk <= (NOT(clk) AND run_simulation) AFTER T_clk / 2;
101
102  -- test process
103  test : PROCESS
104  BEGIN
105    reset <= '1';
106    start <= '0';
107    WAIT FOR 2 * T_clk;
108
109    reset <= '0';
110    FOR i IN 0 TO n_coordinates - 1 LOOP
111
112      IF valid = '0' THEN
113        WAIT UNTIL valid = '1';
114      END IF;
115
116      x <= STD_LOGIC_VECTOR(to_signed(INTEGER(Coordinates(i).x * 2.0 **
117        ↳ floating), N));
117      y <= STD_LOGIC_VECTOR(to_signed(INTEGER(Coordinates(i).y * 2.0 **
118        ↳ floating), N));
119      start <= '1';
120
121      WAIT FOR 5 * T_clk;
122
123      start <= '0';
124      IF valid = '0' THEN
125        WAIT UNTIL valid = '1';
126      END IF;
127
128      WAIT FOR 1 * T_clk;
129      -- Osservazione del valore del modulo e della fase
130      echo("");
131      echo("Test " & INTEGER'image(i) & " X: " &
→ real'image(Coordinates(i).x) & " Y: " &
→ real'image(Coordinates(i).y));
      echo("-----");

```

```

132      echo("Module (Q8.8) = " & real'image(to_real(unsigned(rho), 8)));
133      echo("Phase (Q3.13) = " & real'image(to_real(signed(theta),
134          ↵ 13)));
135      echo("-----");
136      WAIT FOR 10 * T_clk;
137
138      END LOOP;
139
140      run_simulation <= '0';
141      WAIT;
142      END PROCESS;
143  END ARCHITECTURE;

```

Listing 4.1: CORDIC\_tb.vhd

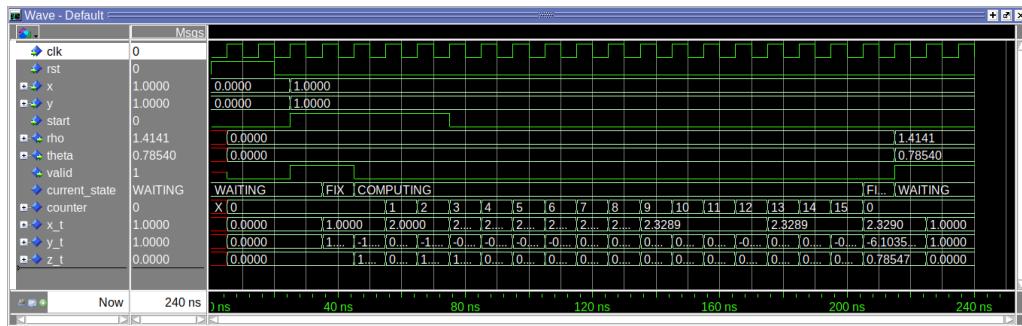


Figure 4.1: Simulation of a single iteration of the testbench

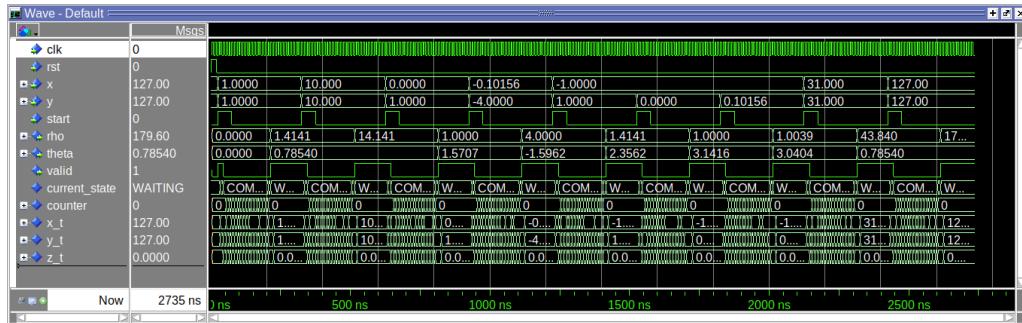


Figure 4.2: Full simulation of the testbench

## 4.2 Graph testbench

This testbench serves the purpose of ensuring the functionality of the circuit over the range of possible inputs. The test was performed on  $512 \times 512$  input points uniformly distributed within the range  $(-128, 128)$  for both  $x$  and  $y$ .

```

1 LIBRARY ieee;
2 USE ieee.std_logic_1164.ALL;
3 USE ieee.numeric_std.ALL;
4 USE ieee.math_real.ALL;
5 USE std.textio.ALL;
6
7 ENTITY GRAPH_tb IS
8   GENERIC (
9     N : POSITIVE := 16;
10    floating : INTEGER := 8 -- (Q8.8)
11  );
12 END ENTITY;
13
14 ARCHITECTURE Behavioral OF GRAPH_tb IS
15
16   -----
17   -- CORDIC component
18   -----
19
20   COMPONENT CORDIC
21     PORT (
22       clk : IN STD_LOGIC;
23       rst : IN STD_LOGIC;
24       x : IN STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
25       y : IN STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
26       start : IN STD_LOGIC;
27       rho : OUT STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
28       theta : OUT STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
29       valid : OUT STD_LOGIC
30     );
31   END COMPONENT;
32
33   -----
34   -- Signals
35   -----
36
37   SIGNAL clk : STD_LOGIC := '0';
38   SIGNAL rst : STD_LOGIC := '0';
39   SIGNAL x_in : STD_LOGIC_VECTOR(N - 1 DOWNTO 0) := (OTHERS => '0');
40   SIGNAL y_in : STD_LOGIC_VECTOR(N - 1 DOWNTO 0) := (OTHERS => '0');
41   SIGNAL start_in : STD_LOGIC := '0';
42   SIGNAL rho_out : STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
43   SIGNAL theta_out : STD_LOGIC_VECTOR(N - 1 DOWNTO 0);
44   SIGNAL valid_out : STD_LOGIC := '0';
45
46   -----
47   -- Simulation parameters
48   -----
49
50   CONSTANT T_clk : TIME := 20 ns; -- clock period = 20 ns
51   CONSTANT SAMPLES : INTEGER := 512; -- samples per dimension
52
53   -----

```

```
54  -- Output file
55  -----
56
57  FILE results_file : text OPEN write_mode IS
58  <-- "cordic_results_512x512.txt";
59
60  -----
61  -- Conversion function from std_logic_vector to real
62
63  FUNCTION to_real(val : unsigned(N - 1 DOWNTO 0); fraction_bits :
64  <-- INTEGER) RETURN real IS
65  BEGIN
66      RETURN real(to_integer(val)) / 2.0 ** fraction_bits;
67  END FUNCTION;
68
69  FUNCTION to_real(val : signed(N - 1 DOWNTO 0); fraction_bits :
70  <-- INTEGER) RETURN real IS
71  BEGIN
72      RETURN real(to_integer(val)) / 2.0 ** fraction_bits;
73  END FUNCTION;
74
75  -----
76  -- CORDIC declaration
77
78  UUT : CORDIC
79  PORT MAP(
80      clk => clk,
81      rst => rst,
82      x => x_in,
83      y => y_in,
84      start => start_in,
85      rho => rho_out,
86      theta => theta_out,
87      valid => valid_out
88  );
89
90  -----
91  -- CLK process
92
93  clk_process : PROCESS
94  BEGIN
95      WHILE run_simulation = '1' LOOP
96          clk <= '1';
97          WAIT FOR T_clk/2;
98          clk <= '0';
99          WAIT FOR T_clk/2;
100     END LOOP;
101     WAIT; -- end process when run_simulation = '0'
102  END PROCESS clk_process;
```

```

104
105  -- Test process
106
107 test_process : PROCESS
108   VARIABLE L : line;
109   VARIABLE real_x, real_y : real;
110   VARIABLE mod_val, phase_val : real;
111 BEGIN
112
113  -- Power on reset
114
115  rst <= '1';
116  start_in <= '0';
117  WAIT FOR 5 * T_clk;
118  rst <= '0';
119  WAIT FOR 5 * T_clk;
120
121
122  -- Loop over (i, j) to test all values
123
124 FOR i IN 0 TO SAMPLES - 1 LOOP
125   FOR j IN 0 TO SAMPLES - 1 LOOP
126
127     real_x := - 128.0 + real(i) * 256.0 / real(SAMPLES);
128     real_y := - 128.0 + real(j) * 256.0 / real(SAMPLES);
129
130     -- Q8.8 Conversion (signed)
131     x_in <= STD_LOGIC_VECTOR(to_signed(INTEGER(floor(real_x * 2.0 **
132       floating)), N));
132     y_in <= STD_LOGIC_VECTOR(to_signed(INTEGER(floor(real_y * 2.0 **
133       floating)), N));
134
135     start_in <= '1';
136     WAIT FOR 2*T_clk;
137     start_in <= '0';
138
139     WAIT UNTIL valid_out = '1';
140     WAIT FOR 10 ns;
141
142     mod_val := to_real(unsigned(rho_out), 8); -- Q8.8
143     phase_val := to_real(signed(theta_out), 13); -- Q3.13
144
145  -- Write on text file: x, y, rho, theta
146
147  -- Comma separated values
148  write(L, real_x, RIGHT, 0, 6);
149  write(L, STRING','');
150  write(L, real_y, RIGHT, 0, 6);
151  write(L, STRING','');
152  write(L, mod_val, RIGHT, 0, 6);
153  write(L, STRING','');
154  write(L, phase_val, RIGHT, 0, 6);

```

```

155      writeline(results_file, L);
156
157      WAIT FOR 1 * T_clk;
158
159      END LOOP;
160  END LOOP;
161
162  -----
163  -- End simulation
164  -----
165  run_simulation <= '0';
166  WAIT;
167  END PROCESS test_process;
168
169 END Behavioral;
```

Listing 4.2: GRAPH\_tb.vhd

## 4.3 Verification

### 4.4 Error verification

The implementation of the CORDIC algorithm in vectoring mode for Cartesian-to-polar conversion demonstrates high accuracy in both module ( $\rho$ ) and phase ( $\theta$ ) outputs. Using a fixed-point representation of  $UQ8.8$  for  $\rho$  and  $Q3.13$  for  $\theta$ , the errors were summarized as follows:

Module Error: Max = 0.004030 units, Mean = 0.001889 units

Phase Error: Max = 0.000154 rad, Mean = 0.000062 rad

Module Error:  $\log_2(\text{Max error}) \approx -7.955$

Phase Error:  $\log_2(\text{Max error}) \approx -12.664$

The observed errors are well within the precision limits of  $2^{-8}$  for  $\rho$  and  $2^{-13}$  for  $\theta$ . For the most part, discrepancies between the expected values and the output values are primarily caused by the conversion of fixed-point representations into real numbers for plotting and analysis.

The 3D plots of module and phase errors visually confirm the bounded and negligible nature of the errors across all tested input combinations. Assuming no error on the input, this analysis validates that the algorithm introduces almost no error in the output.

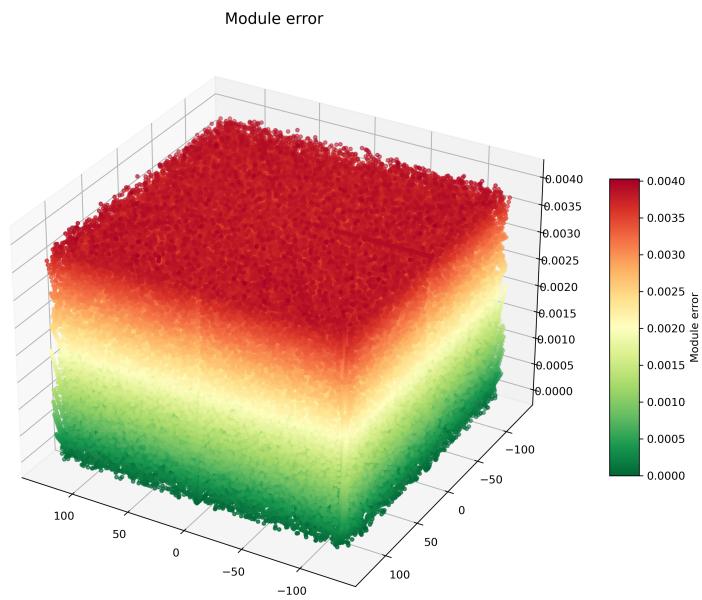


Figure 4.3: 3D plot of module error ( $\rho$ ).

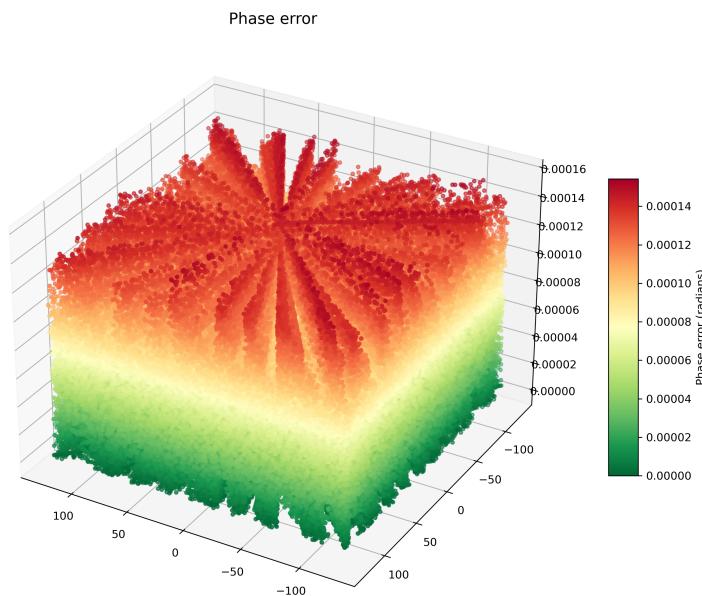


Figure 4.4: 3D plot of phase error ( $\theta$ ).

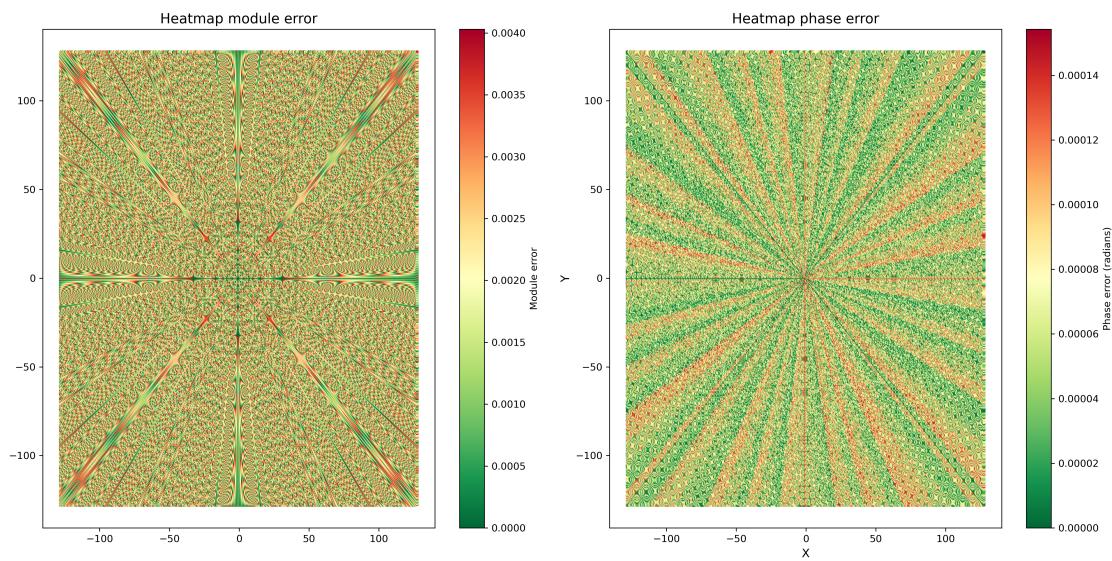


Figure 4.5: Heatmap for phase and module errors.

# 5 Vivado results

After completing the verification phase, the circuit design was synthesized and implemented using the Vivado Tool, specifically targeting the Zybo Zynq-7010 development board.

## 5.1 Vivado Design flow

For the implementation of the CORDIC algorithm in vectoring mode for Cartesian-to-Polar conversion, the Vivado design flow was employed using Xilinx/AMD Vivado software. This process involved RTL Elaboration, Synthesis, and Implementation on the target FPGA, along with the application of design constraints and the extraction of power and timing reports. To ensure accurate and reliable timing analysis, all combinational logic paths were structured to follow a Register-Logic-Register configuration.

## 5.2 RTL

Vivado produced a logic network made of:

1. 155 cells (e.g. multiplexers, DFFs, adders)
2. 68 I/O ports ( $16_x + 16_y + 16_\rho + 16_\theta + 1_{clk} + 1_{rst} + 1_{start} + 1_{valid}$ )
3. 982 nets (for connecting all the components)

The RTL Analysis generated the following Elaborated Design consistent with the expected structure of the system:

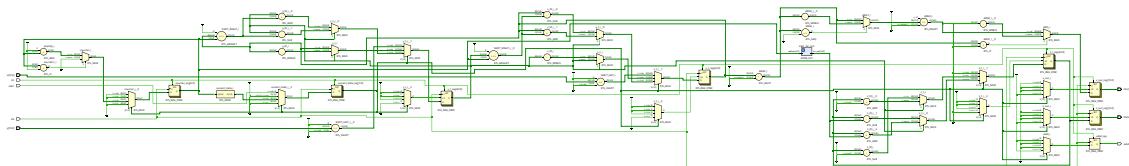


Figure 5.1: Elaborated RTL design.

## 5.3 Synthesis

### 5.3.1 Critical Paths

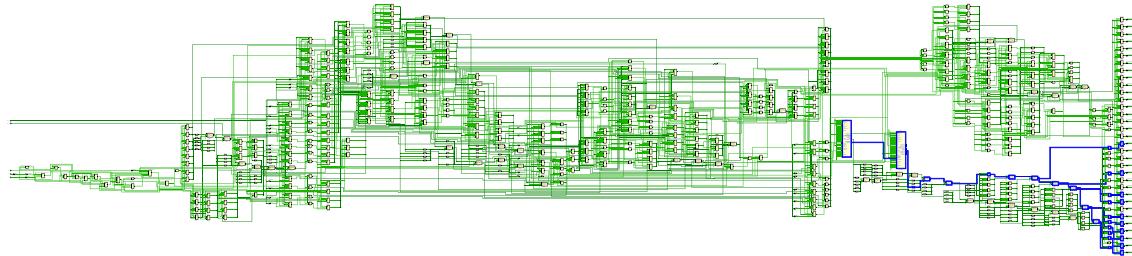


Figure 5.2: Figure showing the elaborated RTL design with the main critical paths for set-up-time-violation found in synthesis step highlighted in blue.

Name	Slack	Levels	Routes	From	To	Total	Delay
Path 1	9.30	12	6	ARG2/CLK	x_out_reg[15]/D	10.55	
Path 2	9.33	11	6	ARG2/CLK	x_out_reg[12]/D	10.52	
Path 3	9.45	10	6	ARG2/CLK	x_out_reg[8]/D	10.40	
Path 4	9.51	12	6	ARG2/CLK	x_out_reg[14]/D	10.33	
Path 5	9.56	9	6	ARG2/CLK	x_out_reg[4]/D	10.28	
Path 6	9.57	11	6	ARG2/CLK	x_out_reg[11]/D	10.28	
Path 7	9.62	12	6	ARG2/CLK	x_out_reg[13]/D	10.23	
Path 8	9.62	11	6	ARG2/CLK	x_out_reg[10]/D	10.23	
Path 9	9.67	8	6	ARG2/CLK	x_out_reg[0]/D	10.18	
Path 10	9.69	10	6	ARG2/CLK	x_out_reg[7]/D	10.16	

Table 5.1: Table showing data of the main critical paths found in synthesis step

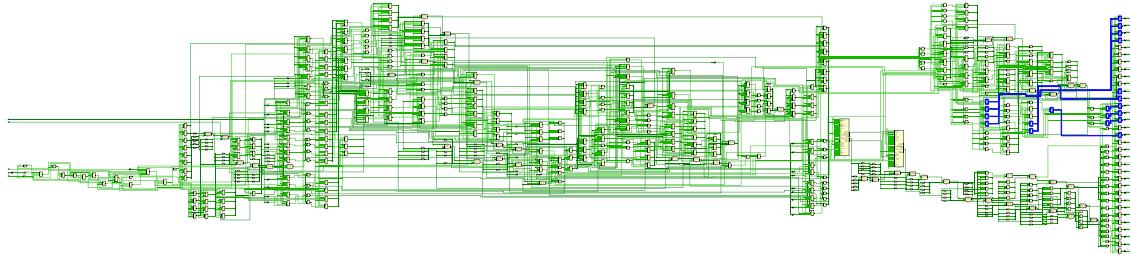


Figure 5.3: Figure showing the elaborated RTL design with the main critical paths for hold-time-violation found in synthesis step highlighted in blue.

Name	Slack	Levels	Routes	From	To	Total Delay
Path 11	0.16	0	1	z_t_reg[23]/C	z_out_reg[15]/D	0.29
Path 12	0.16	0	1	z_t_reg[8]/C	z_out_reg[0]/D	0.29
Path 13	0.16	0	1	z_t_reg[18]/C	z_out_reg[10]/D	0.29
Path 14	0.16	0	1	z_t_reg[19]/C	z_out_reg[11]/D	0.29
Path 15	0.16	0	1	z_t_reg[20]/C	z_out_reg[12]/D	0.29
Path 16	0.16	0	1	z_t_reg[21]/C	z_out_reg[13]/D	0.29
Path 17	0.16	0	1	z_t_reg[22]/C	z_out_reg[14]/D	0.29
Path 18	0.16	0	1	z_t_reg[9]/C	z_out_reg[1]/D	0.29
Path 19	0.16	0	1	z_t_reg[10]/C	z_out_reg[2]/D	0.29
Path 20	0.16	0	1	z_t_reg[11]/C	z_out_reg[3]/D	0.29

Table 5.2: Table showing the characteristics regarding critical paths for hold-time-violation found in synthesis step.

## 5.4 Implementation

Name	Slack	Levels	Routes	From	To	Total Delay
Path 1	8.90	10	3	ARG2/CLK	x_out_reg[9]/D	10.99
Path 2	8.93	10	3	ARG2/CLK	x_out_reg[12]/D	10.96
Path 3	8.99	11	3	ARG2/CLK	x_out_reg[13]/D	10.86
Path 4	9.08	11	3	ARG2/CLK	x_out_reg[15]/D	10.82
Path 5	9.10	9	3	ARG2/CLK	x_out_reg[8]/D	10.84
Path 6	9.10	9	3	ARG2/CLK	x_out_reg[6]/D	10.84
Path 7	9.14	10	3	ARG2/CLK	x_out_reg[10]/D	10.71
Path 8	9.15	9	3	ARG2/CLK	x_out_reg[7]/D	10.74
Path 9	9.18	11	3	ARG2/CLK	x_out_reg[14]/D	10.72
Path 10	9.22	10	3	ARG2/CLK	x_out_reg[11]/D	10.63

Table 5.3: Table showing the main critical paths for the setup-time-violation during the implementation step.

Name	Slack	Levels	Routes	From	To	Total Delay
Path 11	0.17	1	1	counter_reg[0]/C	counter_reg[2]/D	0.31
Path 12	0.17	1	1	counter_reg[0]/C	counter_reg[1]/D	0.31
Path 13	0.18	1	1	counter_reg[0]/C	counter_reg[3]/D	0.31
Path 14	0.22	0	1	z_t_reg[19]/C	z_out_reg[11]/D	0.25
Path 15	0.22	0	1	z_t_reg[23]/C	z_out_reg[15]/D	0.27
Path 16	0.23	0	1	z_t_reg[8]/C	z_out_reg[0]/D	0.26
Path 17	0.25	0	1	z_t_reg[12]/C	z_out_reg[4]/D	0.35
Path 18	0.25	0	1	z_t_reg[22]/C	z_out_reg[14]/D	0.33
Path 19	0.26	1	1	FSM_reg[0]/C	FSM_reg[0]/D	0.35
Path 20	0.27	0	1	z_t_reg[18]/C	z_out_reg[10]/D	0.37

Table 5.4: Table showing the main critical paths for hold-time-violation found in the implementation step.

#### 5.4.1 Utilization Report

Resource	Utilization (%)	Description
Slice LUTs	2.05%	Look-Up Tables used as logic
Slice Registers	0.32%	Registers used in the design
Slice	2.30%	Total slices utilized
LUT as Logic	2.05%	LUTs specifically used as logic
DSPs	2.50%	Digital Signal Processing blocks
Bonded IOB	68.00%	Bonded Input/Output Blocks
BUFGCTRL	3.13%	Global Clock Buffers

Table 5.5: Resource utilization for the CORDIC design (only non-zero values shown)

### 5.4.2 Power Report

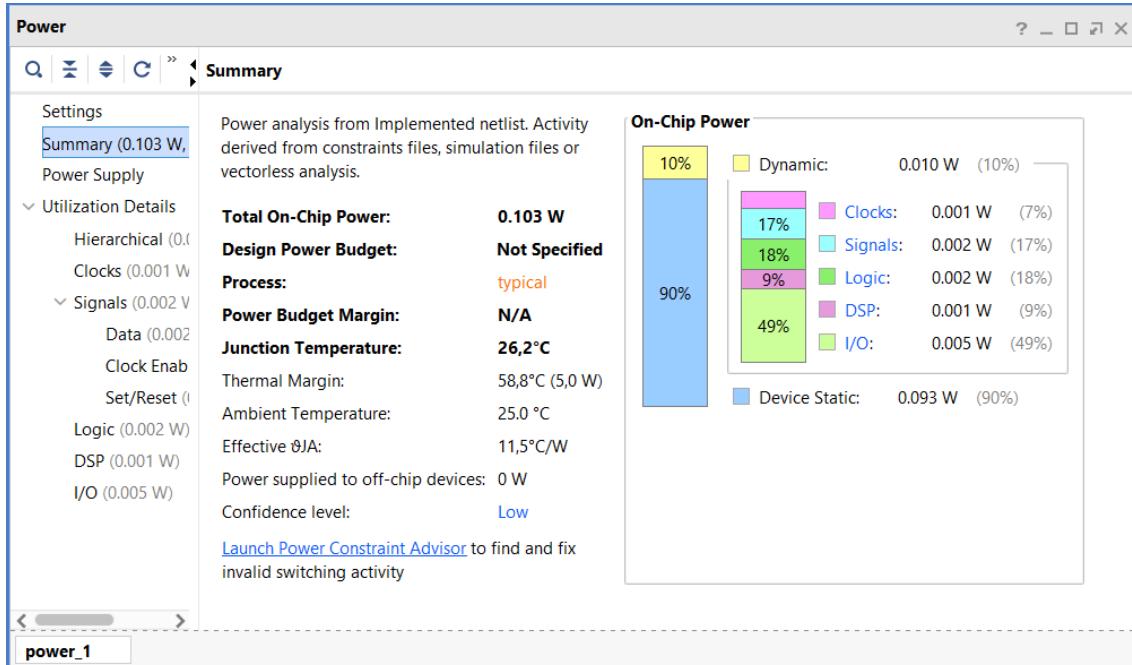


Figure 5.4: Vivado Power Report after implementation.

The power report highlights a total on-chip power consumption of 0.103 W, with 90% attributed to static power (0.093 W) and 10% to dynamic power (0.010 W). The dynamic power is distributed among different components: clocks (7%), signals (17%), logic (18%), DSP (9%), and I/O (49%), with I/O being the highest consumer of dynamic power. It is important to note that this device will not be used alone but is being connected to I/O pins solely for testing purposes.

## 6 Final considerations

The design process adopted in this work demonstrates an efficient approach to implementing the CORDIC algorithm. The iterative methodology ensures high accuracy while maintaining low resource utilization, as confirmed by the Vivado synthesis and power analysis reports.

It is important to note that while the implemented circuit is tailored for the constraints of the Zybo board, the modularity of the design makes it adaptable to other hardware platforms. The testing and verification phase, which included testbenches and graphical analysis, validated the functionality and robustness of the system across a wide range of input conditions.