dfeDataOutputMode

dfeDataOutputMode
1

{

channelCfg

<rxChannelEn>	<txChannelEn>	<cascading>
15	5	0
4 RX channels = Rx4…Rx1	2 TX channels = Tx3, Tx1	no cascading

Baseline_DemoCLIChannelCfg
}
{

adcCfg

<numADCBits>	<adcOutputFmt>	<justification>
2	1	0
16 bits	Complex 2x (image band visible)	left justified

Baseline_DemoCLIADCCfg
}
{

dataFmt,

<adcOutputFmt>	<SampleSwap>	<ChanInterleave>	<chirpThreshold>
0	1	1	1

Baseline_DemoCLIDataFormatCfg
},
{

profileCfg

	<profileId>	<startFreq>	<idleTime>	<adcStartTime>	<rampEndTime>	<txOutPower>	<txPhaseShifter>	<freqSlopeConst>	<txStartTime>	<numAdcSamples>	<digOutSampleRate>	<hpfCornerFreq1>	<hpfCornerFreq2>	<rxGain>
Cli	0	60.75	30	25	59.1	0	0	54.71	1	96	2950	0	0	24
To RL	0	1509949440	3000	2500	5910	0	0	1510.916029	100	96	2950	0	0	24
Details	index 0	60.75Ghz in (2.7*1e9/2^26) units	usec in(10ns) units	usec in (10ns) units	in (10ns) units	0dB for all antennas	0 for all	54.71MHz/usec in (2.7e9*900/2^26) units	1usec in (10ns) units	number of samples	in ksps	175k	350k	dB

Baseline_DemoCLIProfileCfg
}
{

chirpCfg

<startIdx>	<endIdx>	<profileId>	<startFreq>	<freqSlopeVar>	<idleTime>	<adcStartTime>	<txEnable>
0	0	0	0	0	0	0	0x1
			0	0	0	0	0x1
chirpStartIndex	chirpStopIndex	ProfileId	/usec in (2.7e9*900/2^26) u	0Hz/usec in (2.7e9*900/2^26) units	0 sec in (10ns) units	0 sec in (10ns) units	TX1

chirpCfg

<startIdx>	<endIdx>	<profileId>	<startFreq>	<freqSlopeVar>	<idleTime>	<adcStartTime>	<txEnable>
1	1	0	0	0	0	0	0x4
			0	0	0	0	0x4
chirpStartIndex	chirpStopIndex	ProfileId	/usec in (2.7e9*900/2^26) u	0Hz/usec in (2.7e9*900/2^26) units	0 sec in (10ns) units	0 sec in (10ns) units	TX3

Baseline_DemoCLIchirpCfg
}
{

frameCfg

<chirpStartIdx>	<chirpEndIdx>	<numLoops>	<numFrames>	<framePeriodicity>	<triggerSelect>	<frameTriggerDelay>
0	1	128	0	50	1	0
				10000000	1	0
chirpIndex	chirpIndex	chirps in one frame; so 16 for 2 chirps pattern	infinite	msec in (5ns) units	software trigger	0 usec in (5ns) units

Baseline_DemoCLIFrameCfg
}
{
sensorStop
NULL
Baseline_DemoCLISensorStop
}

{

cfarCfg

<cfarMethod>	<cfarDiscardLeft1>	<cfarDiscardRight1>	<cfarDiscardLeft2>	<cfarDiscardRight2>	<refWinSize1>	<refWinSize2>	<guardWinSize1>	<guardWinSize2>	<rangeThre>	<angleThre>	<log2MagFlag>
6	4	4	4	4	16	16	3	6	60	80	0
6: 2-pass range-azimuth CFAR	samples discarded on the left (range)	samples discarded on the right(range)	samples discarded on the left(angle)	samples discarded on the right(angle)	range ref win size	Angle ref win size	range ref guard size	Angle ref guard size	treshold * 10	treshold * 10	log2MagFlag

mmwDemoCfarConfig
}
{

doaCfg

<doaSearchRange>	<doaSearchRes>	<gamma>	<clutterRemovalOn>	<doaDopplerOversamplingFactor>	<doaDopplerSearchUsingCFAR>	<doaDopplerSearchCFARThr>	<doaDopplerSearchCFARGuard>	<doaDopplerSearchSNRReport>
600	1875	30	0	1	1	300	4	2
10*searchBound	1000 * searchRes	1000*gamma	ClutterRemovalFlag	integer oversampling factor	flag to indicate using CFAR for Doppler search	10*DopplerCFARThr	DopplerCFARGuardWinSize	0:report rangeDetSNR, 1: report scaled DopSNR, 2: reportDopSNR

mmwDemoDoaConfig
}
{

trackingCfg

<enableFlag>	<targetType>	<maxMeasPnt>	<maxTracks>	<maxRadialVel>	<velResolution>	<frameRate>	<sensorBoreSigntAnglehorizontal>
1	2	800	20	67	105	50	101
1-enabled; 0-disabled	1-Vehicle;2-People	max num detected points	max num tracks	10*Vr,max	1000 * Vresolution	msec	Angle, in degrees, between sensors' boresight and x-axis (horizontal axis)

mmwDemoTrackingConfig
{
}

classifierCfg

<enableFlag>	<classifierType>	<k>	<codebookSize>	<gamma>	<neighborDistSqrThr>	<gamma1>	<minNpntsPObj>
1	1	1	500	0.6	1	0.95	10
1-enabled; 0-disabled	1:kNN	k value for kNN	500	resistant factor:current_output = previous_output * gamma + current_instantaneous_classifier_tag * (1-gamma)	the minimum sqr distance between 2 targets to declare close neighbor	Close neighbor resistant factor for results smoothing. If a target has at least one close neighbor, use gamma1 instead of gamma for smoothing, gamma1 should be smaller than 1, but much bigger than 0.5, and bigger than gamma.	minimum number of points in the target/track in the current frame to be taken into the statistics for classification

mmwDemoClassifierConfig
{
}