CmpE242

$$\nabla^2 = \frac{\partial^2}{\partial x^2} + \frac{\partial^2}{\partial y^2} \quad \ldots (1)$$

March 10 (Wed)

$$G(x,y) = \frac{1}{\sqrt{2\pi}\,\sigma} e^{-\frac{(x^2+y^2)}{2\sigma^2}} \quad \ldots (2)$$

Note $\mu_x = \mu_y = 0$, $\sigma_x = \sigma_y = \sigma$

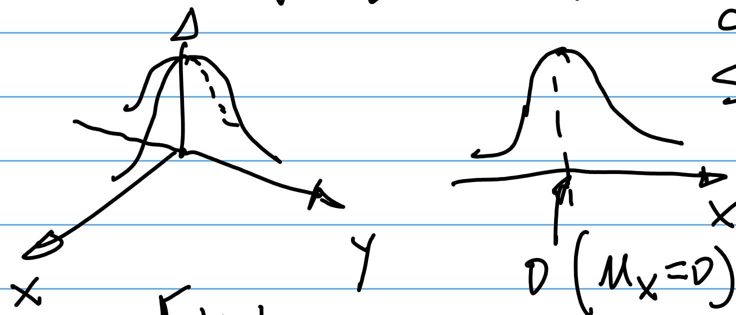


Fig 1.

From Eqn(4), Plot from the github 2018S-15-lec6-V3 ...

Let $y=0$, to have one indep. Variable x.

$$\nabla^2 G(x,y)\Big|_{y=0} = \nabla^2 G(x,0) \quad \ldots (3)$$

$$-\frac{1}{\sqrt{2\pi}\,\sigma^3} e^{-\frac{x^2}{2\sigma^2}} + \frac{x^2}{\sqrt{2\pi}\,\sigma^5} e^{-\frac{x^2}{2\sigma^2}}$$

LoG(x), or $\nabla^2 G(x,0)$

Example: (1) Use LoG(x) to Build a convolutional Kernel (2) to Compute Derivatives of the Error

Note: LoG(x) is NOT Exactly the Computation for derivatives, But we use it, for its Low pass feature, and 2nd order derivative. 22

Sol.,

(1) "Mapping" to a Kernel

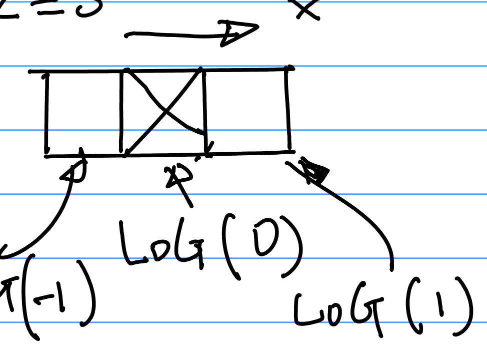
Build a kernel with "odd" Number of grids, elements

$K \times 1$

No. of elements

One Row

for $K=3$



a. Identify the Center Reference

b. from LoG(x) (or $\nabla^2 G(x,0)$), map it to the Kernel

Solve for y ...

Driver Implementation. $\begin{cases} f_{PWM} \\ D.C. \end{cases}$

2018S-10-0 ~
PWM Driver

Add Duty Cycle Function to Device Driver.

$\begin{cases} \text{Theoretical Aspect} \\ \text{Implementation C Code.} \end{cases}$

"T" root

SPRs $\begin{cases} \text{TCON} \leftarrow \text{Control Reg.} \\ \text{TCNT} \leftarrow \text{Counter Reg.} \\ \text{TCMP} \leftarrow \text{Compare Reg.} \end{cases}$

CFG0

CFG1

Prefix "T" imer

PWM Output Square Waveform

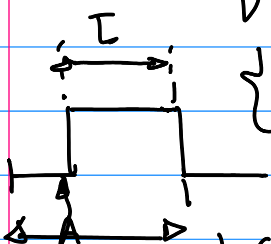


Fig. 1

$T_{PWM} = 1/f_{PWM}$

$$f_{PWM} = \frac{CLK_P}{(\text{Prescaler}+1)(\text{divider})} \quad \ldots (3)$$

PP 1118, CPU Datasheet

Prescaler: 8 bit, [0, 255]

Divider: 1, 2, 4, 8, 16

Note CFG/CON are responsible for Setting Prescaler/Divider value.

$$f_{PWM} = \frac{50\times10^6}{(\text{Pres}+1)\cdot\text{Div.}} \quad \ldots (*)$$

If we need $f_{PWM} = 2\times10^3$

Find SPR, Set SPR to Realize this frequency.

From CPU Datasheet CFG0 CON.

Sol

$$2\times10^3 = \frac{50\times10^6}{(\text{Pres}+1)\text{Div}}$$

$$(\text{Pres}+1)\text{Div} = \frac{50\times10^6}{2\times10^3}$$

$$(\text{Pres}+1)\text{Div.} = 25\times10^3$$

Let Div = 16,

Solve for Pres.

$$\text{Pres}+1 = \frac{25\times10^3}{16}$$

$$\text{Pres} = \frac{25\times10^3 - 16}{16} \simeq > 255$$

Iteration,

Change PCLK to 10 MHz, then, we have

$$Pres = \frac{10\times10^6 - 16\times2\times10^3}{16\times2\times10^3}$$ if it is still too big

therefore, then Low the CLK_p

try $CLK_p \simeq 2\times10^6$. please verify it !

Note: SPR Responsible for f_{PWM}

TCNTB

Timer, Root, Buffer

$f_{PWM} = 1\times10^3$ given.

f ~~master~~ Clock peripherial

N Counts for CNT SPR.

$$f = f_{PWM} \cdot N \quad \ldots (4)$$

Given, Target, Unknown to be Calculated

Note: TCmpB

Comparison Register for Duty Cycle

2nd Counts Value for "Cmp" Derived from Duty Cycle.

March 17 (Wed)

{ f_{PWM} By Setting SPR's

{ Duty Cycle value

Arm 11 ~~Datasheet~~

{ TCNTB ← "N" Counts ↕ f_{PWM}

{ TCmpB

20185-10-

$$f_{PCLK}/f_{PWM} = N \quad \ldots (1)$$

~~Define~~ the period ; CNT

Duty Cycle → % → Counts → Cmp

Percentage

GPFCON PP.522

GPFCON[29:28] = 10 → PWM

GPFCON[31:30] = 10 → PWM

#define S3C64xx_GPFCON

{ 0x7...

*.h

&= ~(0x3u<<28)

"AND", Neg. "00", "11"

|= (0x2u<<28)

"OR", "10", unsigned

Set 2 Bits

GPFCON[29:28] = 10

March 22nd (Mon)
Review.

1° 3± Questions.

a Basic Concepts: CPU Architecture, Block Diagram,
Memory Map, Peripheral Controllers

GPP (GPIO) } SPRs: CON, DAT, ...
PWM } SPRs: PWM, TCNTB, TCMPB, CFG0, 1

Architecture → Mem → SPR
Code

{ User Space Programming
{ Kernel Space Device Driver

Kconf ← Script
Define Compilation + Build Process.

Programming Requirements, No Program Code Writing

However! Debug/Change the existing Code is Needed;

b Design Related Question(s)

SCH. Design, CKT for PWM, GPIO

Pin(s), f_{PWM}

Motor Drive
Pin(s), Label(s) Stepper motor I/F

GPP I/O Testing ("Hello, the World")

{ Input Testing CKT
{ Output Testing CKT

Resistance Value Calculation

c Theoretical Aspects

C1. PID Controller Design
Basic Concepts
Block Diagram.

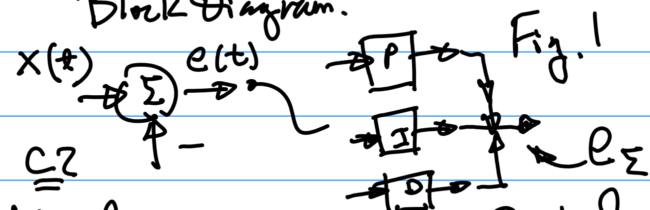


Fig. 1

C2
Kernels: F.D. 2x1 → Central D. $\frac{1}{2}$(F.D+B.D)
B.D. 2x1

With Noise Reduction 3x1
Low Pass Filter: G(x) Gaussian.
+ 2nd Order Derivation as in Computer Vision

∇^2: Laplacian $\frac{\partial^2}{\partial x^2}+\frac{\partial^2}{\partial y^2}$ → 1D $\frac{\partial^2}{\partial x}$

LoG(x)

Note: One page formula sheet is Allowed, However No verbal Description And/Or Examples Allowed.

Note: Calculator Is Allowed.

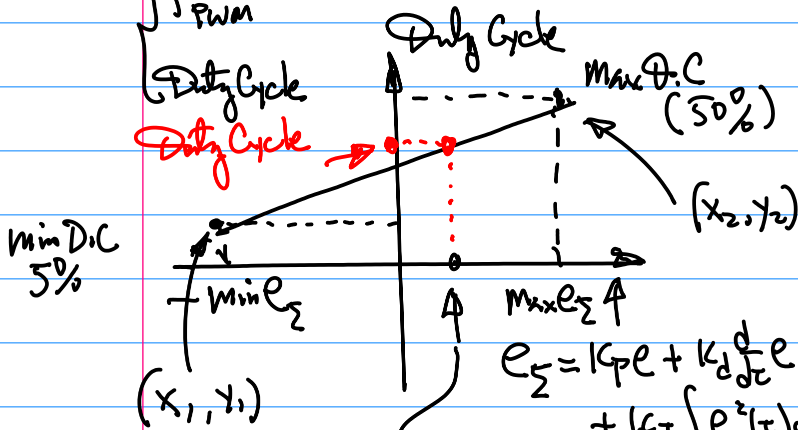
Close Book, Close Notes
Datasheets if needed will be provided;

Convolution with Kernel(s)
Table of E(t), find $\frac{d}{dt}E(t)$ Convolution

$\int K_I e^2(\tau)d\tau \simeq \sum_{i=0}^{I} K_I e^2(\tau)$

Mapping to Control function PWM

$\begin{cases} f_{PWM} \\ \text{Duty Cycle} \end{cases}$



$e_\Sigma = K_p e + K_d \frac{d}{dt}e + K_I \int_I e^2(\tau)d\tau$

find control Action, $e_\Sigma = 0.57$ → D.C = ?

Implementation: Reference Platform ARM11

Architecture
CPU Block Diagram → Memory map.

2^{32} (4 GB)

8 Equal Bank

↓ 3 Addr. Bits

$a_{31} a_{30} a_{29}$

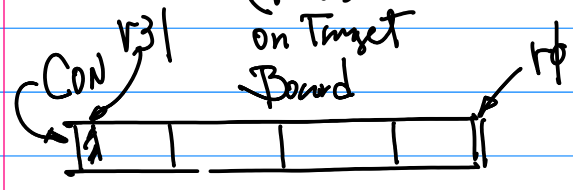
* SPRs. ←

(Peripheral Controllers)

$\begin{cases} \text{PWM} \\ \text{GPP} \end{cases}$

GPx CON
GPx DAT
T CNT B
T CMP B

Design Spec. → SPRs (pins) on Target Board → CPU Datasheet



To perform init & Config:
1° Binary Pattern for SPR.

Read/modify user Application Programs / Kernel Space Device Driver Program.

C Code for this purpose.

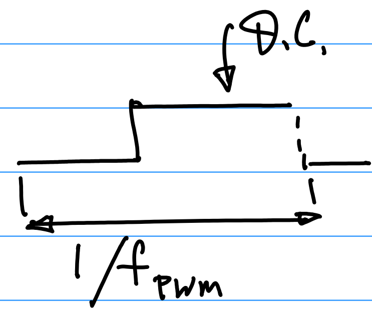
Note: PWM Waveform, e.g. Duty Cycle Calculation.

N. for CNT
N' for CMP
T B

$f_{PCLK} / f_{PWM} = N$

$f_{PWM} = \frac{PCLK}{(Prest+1) * DVR}$

%(D.C) * N = N' → Cmp



Prerequisit
1° O.S Source Distribution
2° Tool Chain Distro. "Cross Comp"
3° Datasheet.

↓

Tool Chain Installed Running

make menuconfig

Continued → Kconf (at \drivers \char)

↓

Script. Add your Device Driver

↓

make menuconfig

↓

invoke your change, Compile & Build (Module Only for Simplicity Purpose)

↓

Object "ko".

↓

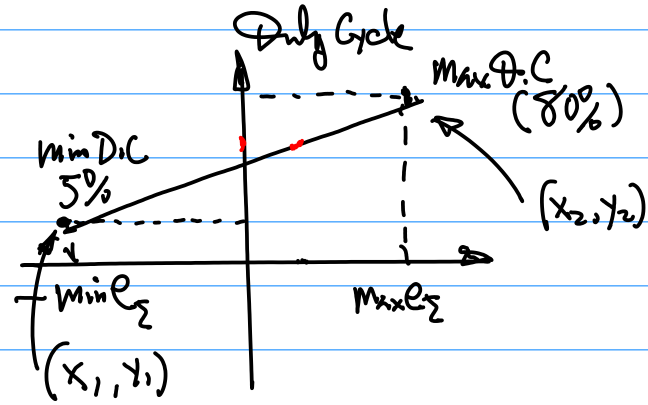
Copy "usb" upload by "cp" Copy Command to your target

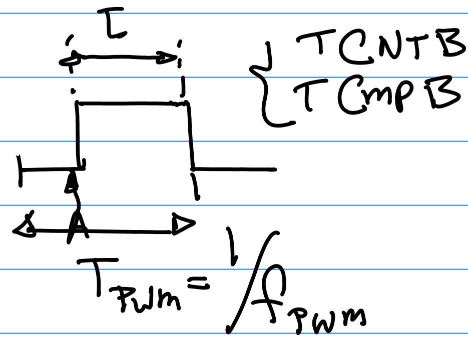
↓

"insmod" mytest.ko (To make it as a part of Kernel Image)

↓

run your user application program (By calling the module)





https://github.com/hualili/CMPE242-Embedded-Systems-/blob/master/2018S/16-AngularSensing-i2c-L8

CMPE/EE242

32

April 5th (Monday)

1. midterm Graded, the key was posted online, github, search under folder 2019S, "Key"

2. 2nd half of this Course. IIoT (Industrial IoT)

Sensors I/F { Digital Sensors — I2C I/F. / Analog Sensors — ADC

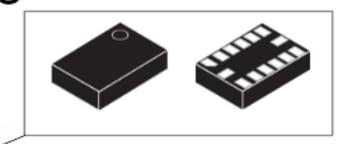
FFT to find/Characterize Analog Sensor Data (Nyquist Theorem) Validation of Sensor Data.

OpAmps to Build Processing CKT. "SPICE" Simulation.

CMPE242-Embedded-Systems- / 2018S-16-AngularSensing-i2c-LSM303- final HL 2017-3-13.pdf

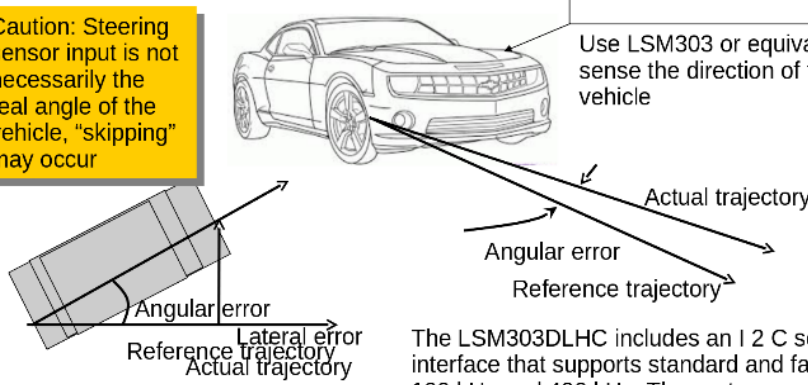
Sensors for Driving Direction and Turning Angle

eCompass module:
3D accelerometer and 3D magnetometer



Use LSM303 or equivalent to sense the direction of the vehicle

Caution: Steering sensor input is not necessarily the real angle of the vehicle, "skipping" may occur



The LSM303DLHC includes an I 2 C serial bus interface that supports standard and fast mode 100 kHz and 400 kHz. The system can be configured to generate interrupt signals by inertial wake-up/free-fall events as well as by the position of the device itself.

Harry Li, Ph.D. April 2015

Example: LSM303

Note: Next Project use LSM303.

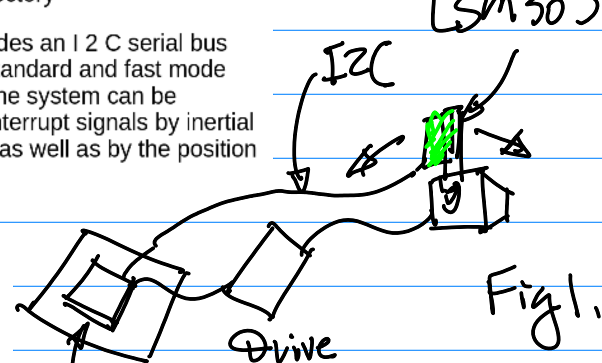
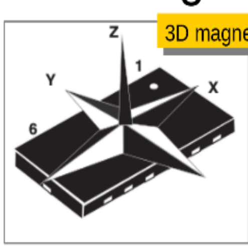


Fig 1.

Configuration I for PID controller

3D Accelerometer and 3D Magnetomete LMS303



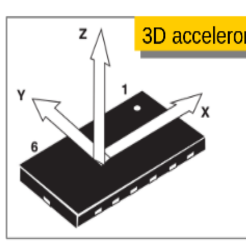


Table 9

Pin name	Pin description
SCL	I^2C serial clock (SCL)
SDA	I^2C serial data (SDA)

I2C Interface

(1) The transaction started through a START (ST) signal, defined as a high-to-low on the data line while the SCL line is held high.
(2) After ST, the next byte contains the slave address (the first 7 bit), bit 8 for if the master is receiving or transmitting data.

Homework: Implementation I2C LSM303 Sensor I/F. Due April 16 (Fri)

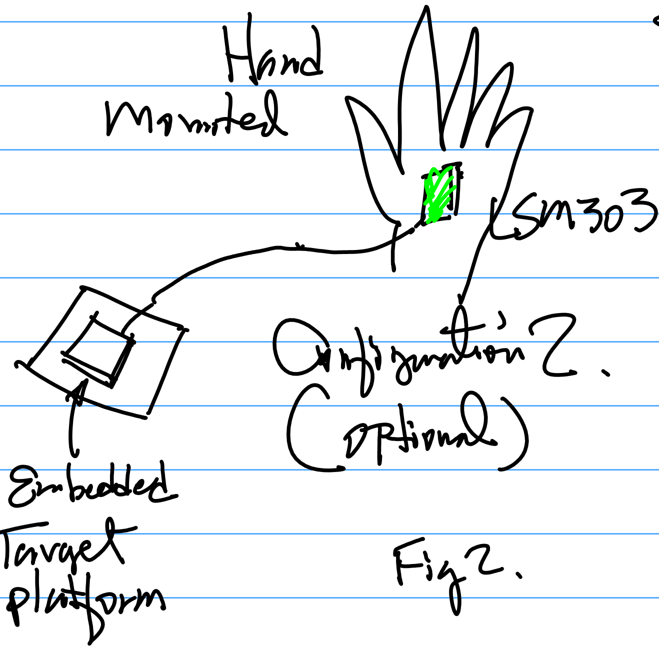


Fig2.

3. a Space-Time Diagram

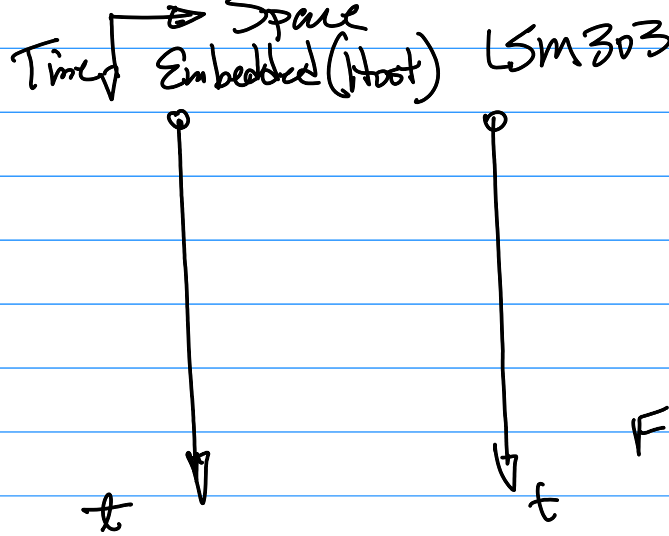


Fig3

Submission On Canvas

Objective ① To be Able to Read Sensor Input,

② To be Able Config the Sensor.

b To Describe "Hand-Shaking"

Three Small steps.

Step 1. → Step 2 → Step 3

Host Command. to the Target via Address for Init & Config

Slave "Ack"

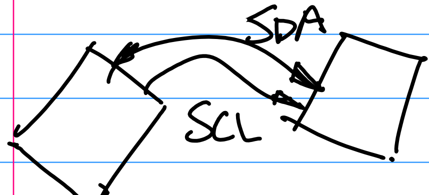
Data Transmission will start

1. Note: LSM303 for ST-micro

Sensor Supports { Acceleration X-Y-Z axis, Magnetometer, Temperature

2. I2C

{ SDA (Serial Data) Bidirectional Data;
{ SCL (Serial clock)



Embedded platform

I2C Device (LSM303)

Fig4.

* Be sure read Datasheet to map the Steps of the I/F to Space-Time Diagram.

3. Datasheet Table 9 & 11.

Pg. 20.

Notation:

A Frame

1° ST → SP

"Start" "Stop"

2° The Notations in Table 11
SAD, SAD+W, SUB, DATA,
SAK. etc. pp. 20

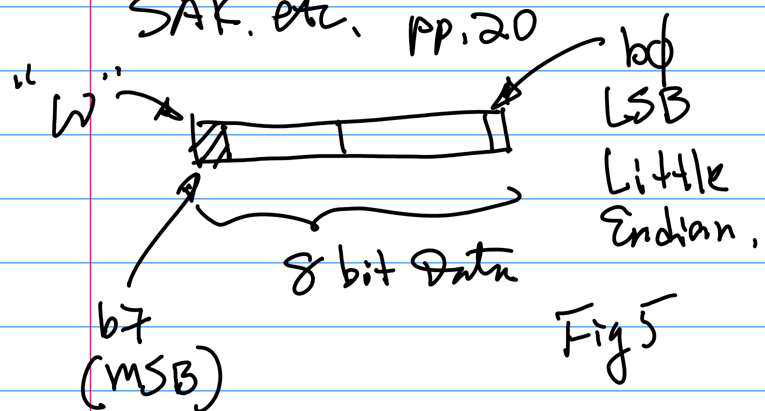
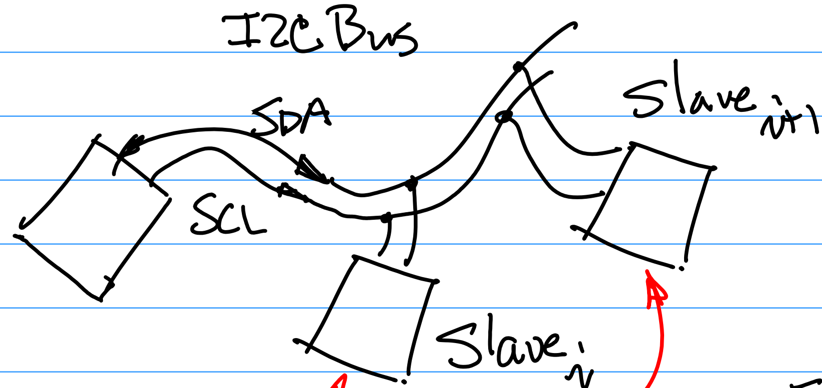


Fig 5

3° from pp. 20 (Datasheet)



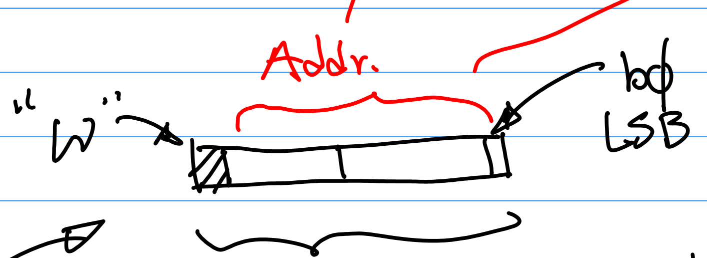
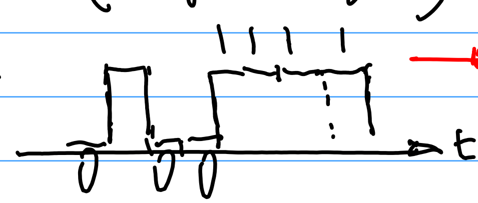


Fig 6

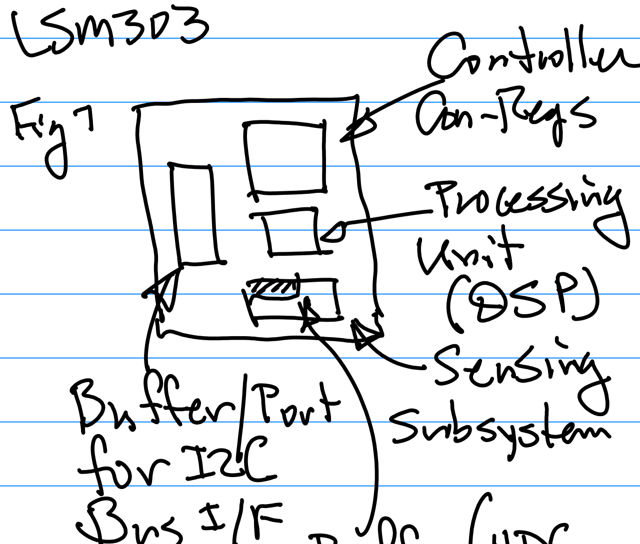
4° 1st Address (7 bits) lower, 2nd Address SUB.
All from the host (Target platform)

0xf2
1111 : 0010



Consider A slave device
LSM303

Fig 7



2nd Address "SUB"
is for Identifying the
target inside the
Slave Device.

5. 127 Devices Possible
(Theoretically) on
I2C Bus, In Reality
this has to Checked
By "FAN-IN" "FAN-OUT"

128 Internal Addresses
→ Special Purpose
Registers.

6. Most Significant Bit is
transmitted first

Example: From Datasheet (LSM303) PP.19 Table 11, 12, 13

Homework (1pt) Due A week from Today, April 14, Due On CANVAS

1° Build I2C Bus Interface with your target platform as a host, LSM303 Slave. To be able:

a Hardware Implementation. (e.g. mount LSM303 on the Stepper motor, OR mount it to your hand)

b Read Acceleration Data X, Y, Z, Display it On your terminal.

c Read Magnetometer Data and display it on the terminal

Note: Sample code is posted "as is" basis.

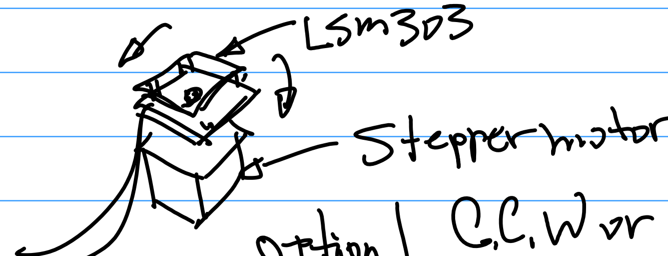
Repo: 20-2021S-10-lsm

2° Submission

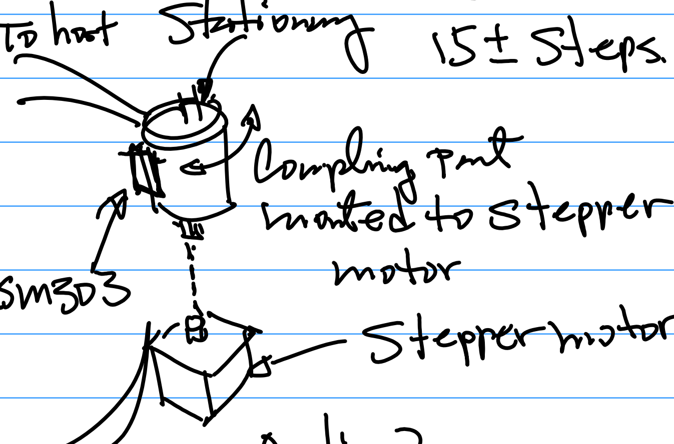
a Source Code, b Readme.txt

c photo(s) of your Implementation

3x photos, 1 for the entire System (with Laptop); 2nd for the Host Side, Expansion Connector is the focus; 3rd for LSM303



Option 1. C.C.W or C.W. 15± Steps.



Option 2.

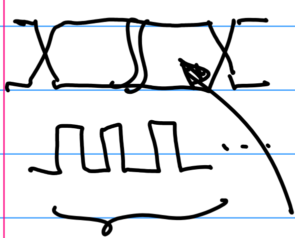
d 5 seconds Video Clip(s) 720P OR 1080P (1920x1280) Compressed, mpeg4, .avi ?

file Naming: firstName_4Digits_242.zip

Note: Table 11 & 12 (PP19)

One Byte Writing → Multiple Bytes Writing
Host — Host

Table (Logical Behavior)
↓
Timing (Waveform)



Now, the Address for the Sensor(s)
and Addresses for Registers
- Control Register — Init & Config
- Data Register

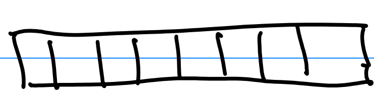
SAD[7:1] Address + SAD[0] for W/R
- =1 for W
- =0 for R

Note: Use info from Table 14
to fill in SAD+W, SAD+R
in tables 11~13.

Note: Section 5.1.3 Magnetometer

Example: Table 18. Control Register A
for Magnet

CTRL_REG1_A [7:0] 8 bits.



CTRL_REG1_A[7:4]=0x7
(for 400Hz)

Tech Spec → Binary Pattern

Tech Spec:
i. 400Hz Data Rate
ii. X-Y axis.
iii. Sensor Active (No Low Power)

CTRL_REG1_A [3]=0
CTRL_REG1_A [2]=0
CTRL_REG1_A [1]=1
CTRL_REG1_A [0]=1
→ 0x3

Hence,
CTRL_REG1_A [7:0] =
0x73 ✓

Section 7.1.8 Status Registers
Section 7.1.9 ~ 7.1.11
Data Registers.
2's Complement form
↓
1's Complement By Negation
"0" → "1"
"1" → "0"
+1

April 12 (Monday)

Homework Extension to April 19 (Monday)

Industrial Analog Sensor I/F Design

Example: NH_3 Analog Sensor (Ion Selective Electrode) Interface.

1. ADC (Analog to Digital Conversion Unit)

LPC1769 6x ADC

ARM11 ADC

Pie Stand Alone ADC

Jetson NANO/TX2

1° Sampling Rate
500 KSPS

2° Quantization
8 bits, 10 bits, 12 bits.

3° SPI / I2C
Faster ≤100MHz ≤10MHz

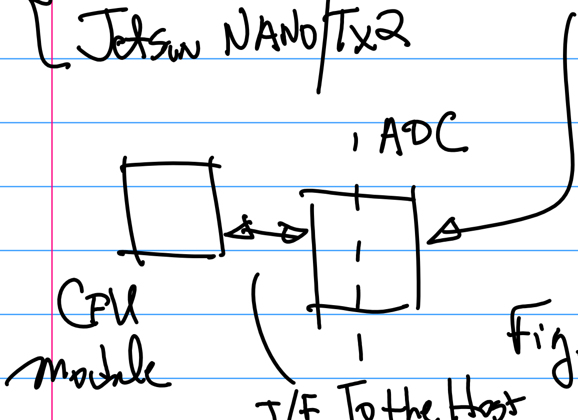


Fig. 1

2. Prototype to Build

Stepper motor Drive

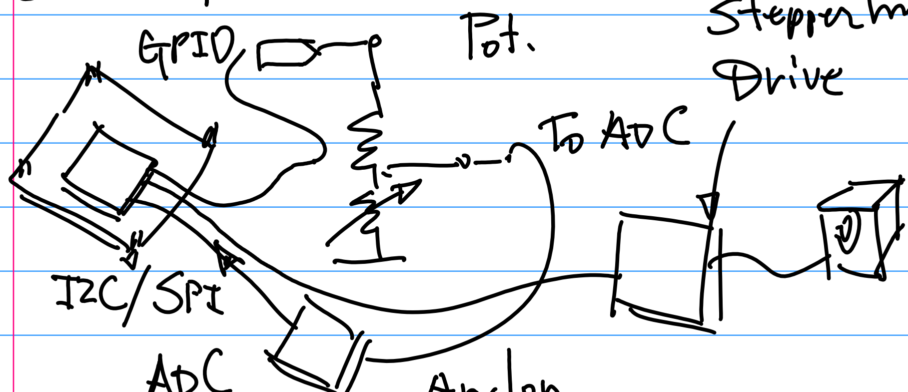


Fig 2.

3. Analog Interface Design.

Start with Characteristic Curve

↓

Linearization

↓

OpAmp Preprocessing CKT

↓

Optimized dynamic (Input) Range to ADC

4. OpAmp's for Preprocessing

- Addition
- Subtraction
- Division
- multiplication

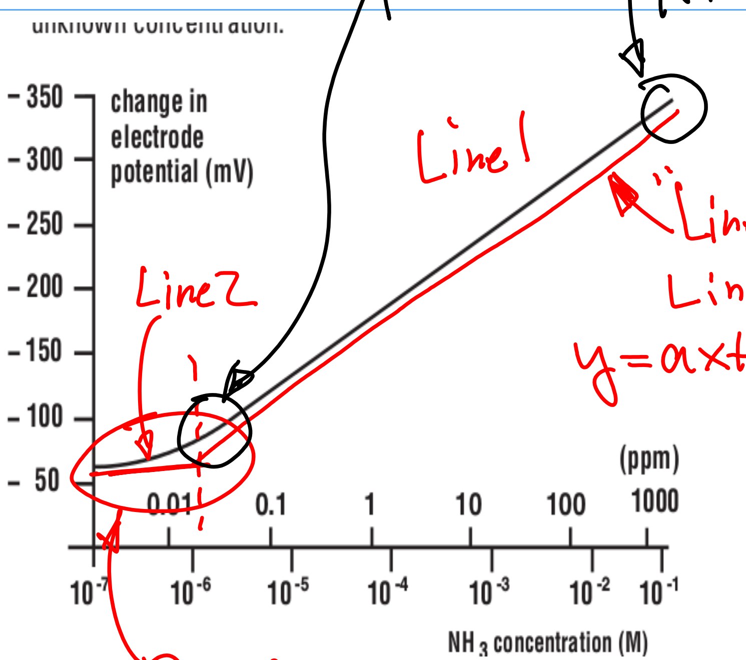
Math. Operations for Preprocessing

Example: from Datasheet 2018S-22-NH3- TP13, Fig. 14.

Step1. Linearization Characteristic Curve

Starting pt.

Ending pt.



Line 1

"Linear" Line

$y = ax + b$

Line 2

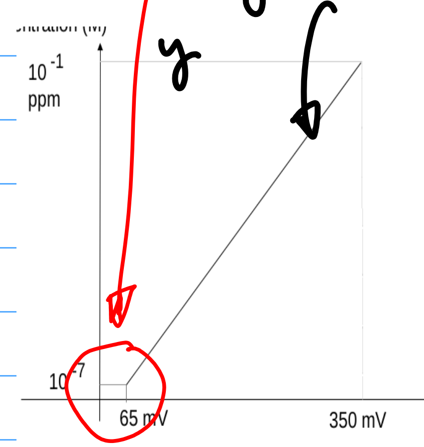
Curve

Non-Linear. $y = ax^2 + bx + C$ 2nd order

Step 2. Map the Dynamic Range of Sensor Output to the Dynamic Range of ADC Input.

2.1 "Shifting" OR Offset to move the Characteristic Curve to the origin.

$y = ax + b$



y

x

Linearization: Line Equation(s) to Replace Non-Linear Curve.

Simplification: Just Keep Line 1.

Note: Linearization By Identifying Starting and Ending Points.

(V_0, C_0) (V_N, C_N)

Voltage V.S. Concentration

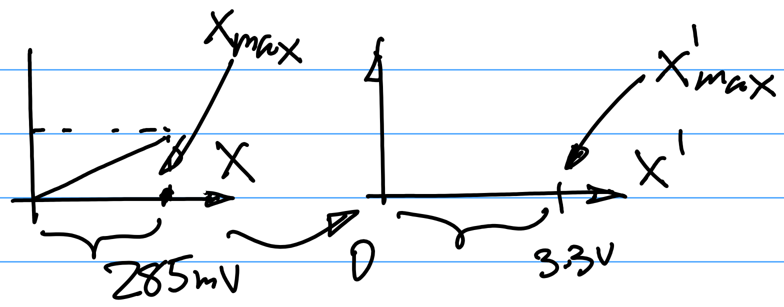
$$\frac{X - X_1}{X_2 - X_1} = \frac{Y - Y_1}{Y_2 - Y_1} \quad \cdots (1)$$

$(X_1, Y_1) \rightarrow (V_0, C_0)$, $(X_2, Y_2) \rightarrow (V_N, C_N)$

X_{New} is changed By "Shifting"

$aX \rightarrow a(X - \Delta X)$

2.2 Dynamic Range fits to ADC Dynamic Range



$$\frac{X'_{max}}{X_{max}} = \frac{3.3V}{0.285V} \overset{Let}{=} A \quad \cdots (2)$$

Gain

("Scaling Factor")

$$X \cdot A = X' \quad \cdots (3)$$

Review OpAmp { Inverting Configuration OpAmps
Non-Inverting Configuration

April 14 (Th).

OpAmps for Pre-processing Design

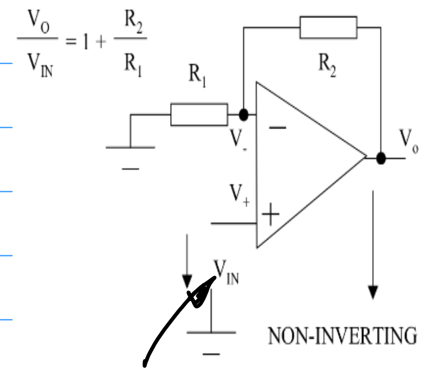
1. OpAmp {
   - a Very High Input Impedance
   - b Very Big Open-Loop Gain
   - c Very Small output Resistance

2. Using OpAmps As Basic Building Blocks (B^3) for

   Arithmetic Computation { Add/Sub
   Multiplication/Division

   Integral/Derivatives

3. Configurations { Non-Inverting ~
   Inverting ~

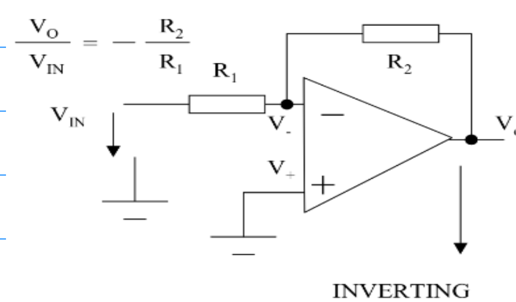


a Input: Positive Polarity;

b feedback CKT
$V_{out} \to$ Input (V_- pin)
via R_f

c Draw the CKT.

$$A = V_{out}/V_{in} = 1 + R_f/R_1 \quad \cdots (1)$$



a Input: V_- pin

b feedback CKT
$V_o \to V_-$(in) via R_f

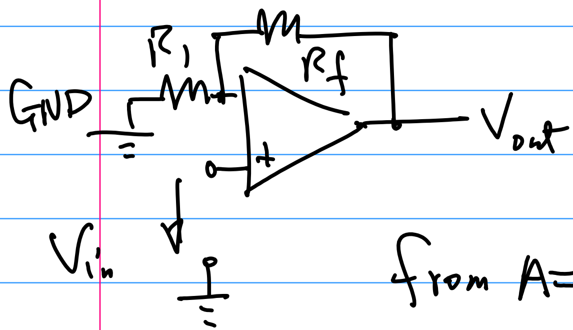
c $A = -\frac{R_f}{R_1} \quad \cdots (2)$

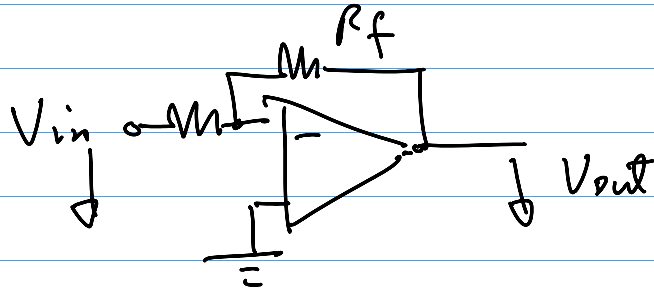
4. Use OpAmp CKT(s) for Math. Operations.

More than One Approach is possible, But Let's use Inverting Configuration

a Addition. $X_1 + X_2$

Non-Inverting Configuration

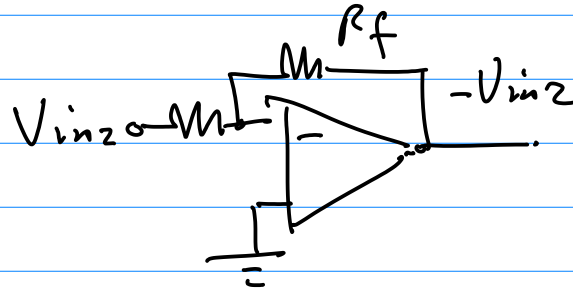




from $A = 1 + \frac{R_f}{R_1}$

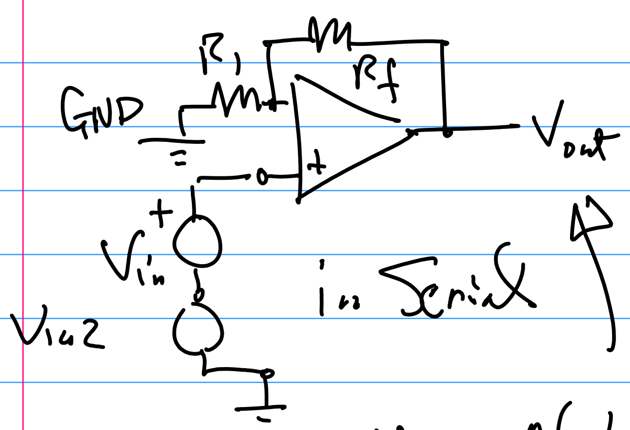
$\frac{V_{out}}{V_{in}} = A = -\frac{R_f}{R_1}$

OR, $A = V_{out}/V_{in}$, $V_{out} = A \cdot V_{in}$ ...(3)



$V_{in1} + V_{in2}$ Addition

Let input Circuit as follows



make $V_{out} = -V_{in2}$, Let $R_f = R_1 = 1K\Omega$

(741 opAmp, 384 Quad-Pack)

Note: Not too Big Current, PWR Consumption is going to be a problem.

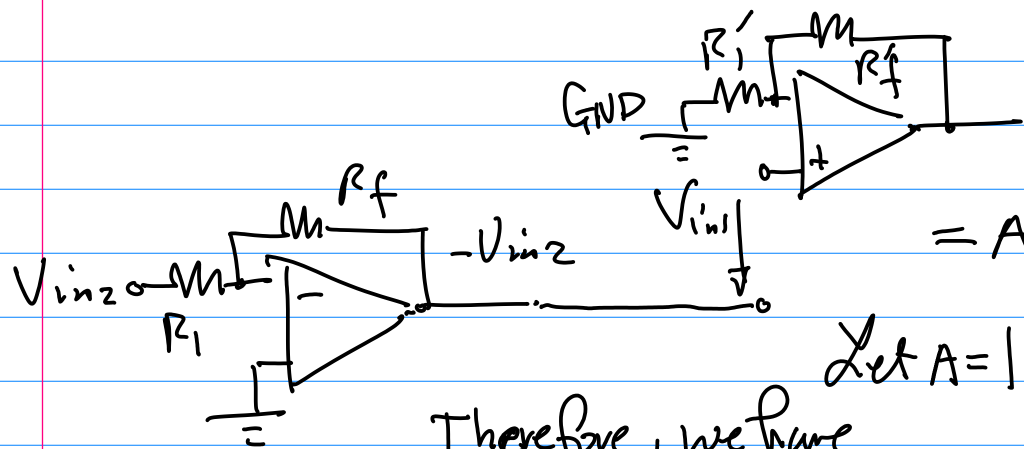
Not too small, Noise will distore the Signal

$V_{out} = A(V_{in1} + V_{in2})$

Let $A = 1$, $\Rightarrow R_f = 0\Omega$

b Subtraction $X_1 - X_2$ $(V_{in1} - V_{in2})$

Then, Combine it with Add CKT
So, we have $V_{in_1} - V_{in_2}$



$V_{out} = A\,V_{in}$

$= A(V_{in_1} - V_{in_2})$

Let $A = 1$, Hence $R_f' = 0\Omega$

Therefore, we have

Subtraction

$V_{out} = V_{in_1} - V_{in_2}$

c. multiplication. $y = ax$, $a > 1$

use Non-Inverting Configuration

$$\frac{V_{out}}{V_{in}} = A \Bigg|_{A = 1 + \frac{R_f}{R_1}}$$

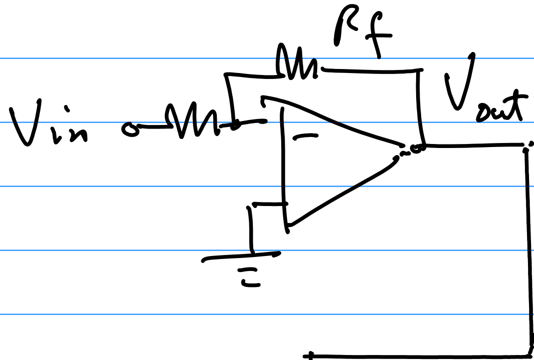
$$V_{out} = A \cdot V_{in} = \left(1 + \frac{R_f}{R_1}\right) V_{in}$$

Note: For Linear System, the multiplication is done by multiplying a gain, But Not Another X (or V_{in}).

d. Division (is a multiplication!) for the multiplier A less than 1.

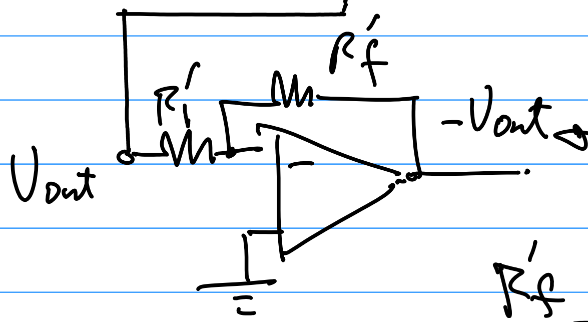
Two Stage Inverting Configuration, 1st Stage does the division But with negative Sign, 2nd stage with gain = 1, But Change to positive by 2nd negative.

Example: 2 stage Inverting



$V_{out} = -\frac{R_f}{R_1} V_{in}$, where $\frac{R_f}{R_1}$ is a fractional Number for division, for example 0.32, $R_f/R_1 = 0.32$, if $R_1 = 1K$

$R_f = 320\Omega$



to make gain = -1

$\frac{R_f'}{R_1'} = 1$, Let $R_1' = 1K\Omega$, then Solve for

$R_f' = R_1' = 1 K\Omega$.

//

Project Due May 9 (Sunday) 11:59 P.m.

Note: Analog Sensors have to meet the Output Current Requirement, e.g. 4~20mA //

April 19 (Mon).

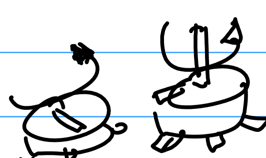
1° Preparation for the Coming Project. Fig 2, PP.37.

April 19 (Mon)

Design ON Preprocessing CKT.

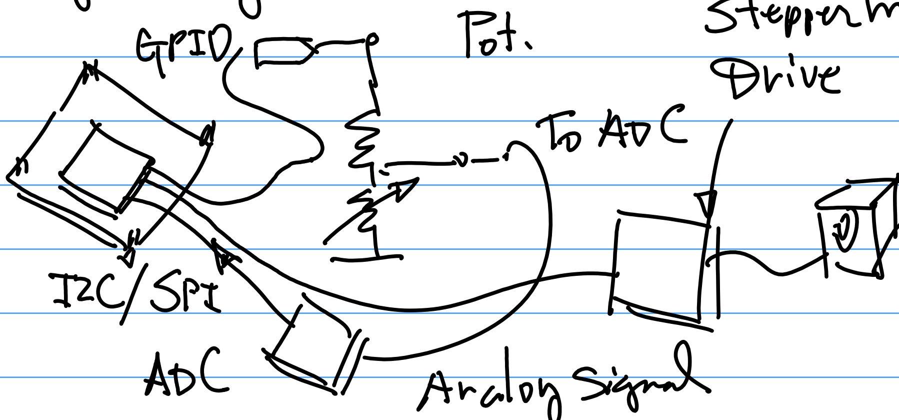
Example: See Fig. on github

Characteristic Curve.



Stepper motor Drive

Shifting → Enlargement of the Dynamic Range.



a Shifting. Add/Sub.

b Dynamic Range: Gain mult.

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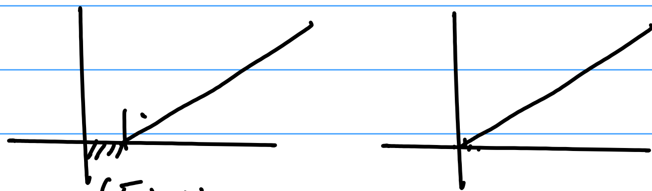
Shifting (Subtraction).



65mV

Inverting Configuration

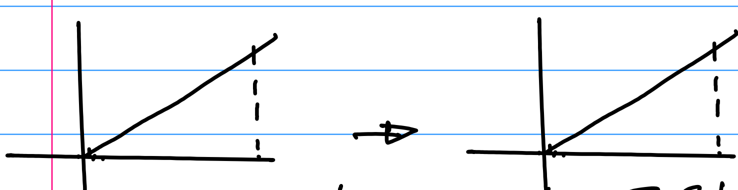
$$\frac{V_o}{V_{in}} = -\frac{R_f}{R_1}$$

Desired Shifting

Output from the Reference (External Voltage Source)

$$\frac{65 \times 10^{-3}}{5.0} = \frac{R_f}{R_1}, \quad \text{Let } R_f = 1K\Omega \quad \cdots (1)$$

Now, Dynamic Range Design



285mV 3.3V.

$$\text{Gain} = \frac{3.3V}{285mV} = \frac{3.3}{0.285} \simeq 11.58 \quad \cdots (2)$$

After

Before

Since Gain is positive, we have Non-inverting configuration

$A = \left(1 + \frac{R_f}{R_1}\right)$, substitute (2) into this Eqn.

$11.58 = 1 + \frac{R_f}{R_1}$

Let $R_1 = 1K\Omega$, find/solve for R_f. Hence $R_f = 10.58 K\Omega$

Then, Integrate OPAmps Together to form Preprocessing CKT.

Note:

1° Analyze Sensor Characteristic Curve, Define Arithematic/Math Operations, for Shifting and magnification (of the Gain, to Cover 3.3V Dynamic Range)

2° To be Able to use Inverting And/OR Non-inverting Configuration to Realize the design Requirements, e.g. Shifting, and magnification

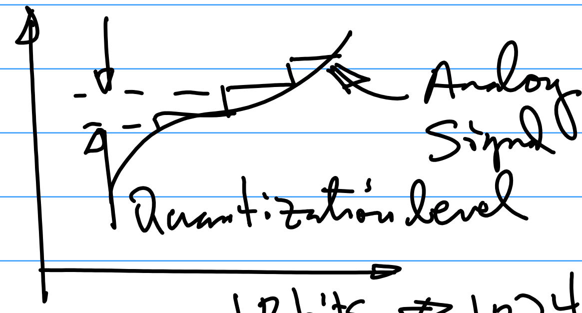
Now, Let's Consider the ADC Design. Scope:

- System Level for ADC
- Data Validation

D.F.T. (Discrete Fourier Transform) → Power Spectrum

↓

Nyquist Sampling Theorem.

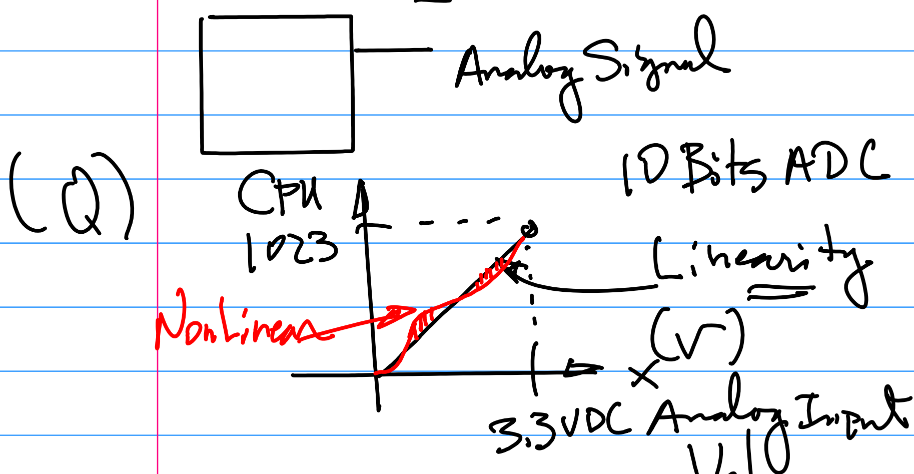


10 bits → 1024 $= 2^{10}$

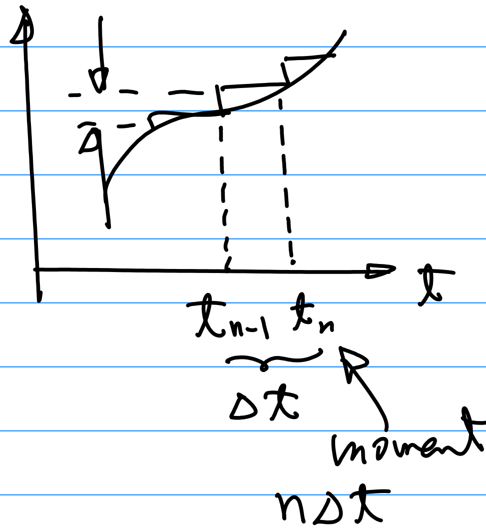
Δt : Sampling interval

April 21 (Wed)

Data Validation : To make sure ADC Output (to CPU)



$\Delta Q / \Delta V = K$



→ Nyquist Theorem

$$f_{sampling} \geq 2 f_{max} \quad \cdots (1)$$

Sampling frequency has to be greater than OR Equal to Twice the highest frequency of the Signal itself.

Note:

1. Denote Digital signal as $x(n)$ or $x(k)$

Digitized, limited Quantization level

Index integer nΔt

2. Introduce Discrete Fourier Transform

a. Background : Basic Building Blocks to Characterize or to Build a given Signal.

↓

Fourier Transform

b. Formulation.

$$C_n = \int_T x(\tau) e^{-j2\pi f \tau} d\tau \quad \ldots (1)$$

$$f(x) = f(x_0) + \frac{f'(x)}{1!}(x-x_0) + \frac{f''(x)}{2!}(x-x_0)^2 + \cdots + R_n(x) \quad \ldots (2)$$

Basic Building Blocks

$$f(x) \cong \sum_{n=-\infty}^{+\infty} C_n(\cos 2\pi n f t + \phi) \quad \ldots (3)$$

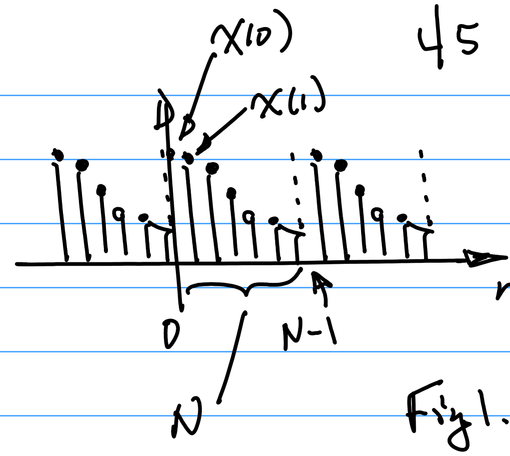


Fig 1.

$n=0,\ n=1,\ n=2,\ \ldots$

$x(0),\ x(1),\ x(2),\ \ldots$

$e^{-j2\pi\frac{mn}{N}}$ for Imaginary Axis

3. Notation

$X(m)$ Discrete Fourier Transform of a Signal $x(n)$

m : Index in Frequency Domain

m : Frequency Index

$X(m)\big|_{m=0} = X(0)$ D.C. Component

$X(1), X(2), \ldots X(N-1)$ Higher Freq. Comp.

Hence, D.F.T. (Discrete Fourier Transform)

$$X(m) = \frac{1}{N}\sum_{n=0}^{N-1} x(n) e^{-j2\pi\frac{mn}{N}} \quad \ldots (4)$$

$$X(m) = \sum_{n=0}^{N-1} x(n) e^{-j2\pi\frac{mn}{N}}$$

$$= x(0)e^{-j2\pi\frac{m\cdot 0}{N}} + x(1)e^{-j2\pi\frac{m\cdot 1}{N}} + \cdots + x(N-1)e^{-j2\pi\frac{m(N-1)}{N}}$$

from Right Hand Side of Eq.(4).

(For Simplicity, $\frac{1}{N}$ Removed)

Physical meaning:

$x(n) = x(n+kN)$ periodic function.

Period : N, where $k = 0, 1, 2, \ldots$ (Natural Number)

$\frac{1}{N}$ Scaling factor, N No. of Total pts for One Period.

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Note: Final Exam

— May 21 (Fri)

1215–1430

for $m=0$,

$$X(0) = x(0)e^{-j2\pi\frac{0\cdot 0}{N}} + x(1)e^{-j2\pi\frac{0\cdot 1}{N}} + \cdots + x(N-1)e^{-j2\pi\frac{0(N-1)}{N}}$$

D.C.

$$= x(0)\cdot 1 + x(1)\cdot 1 + \cdots + x(N-1)\cdot 1$$

$$= \underbrace{x(0) + x(1) + \cdots + x(N-1)}$$

Divided by $1/N$, Average → D.C.

Example: Eqn (5)

Left Hand: $X(m)$

D.F.T. $\quad m$ Freq. Index

$m = 0, \underbrace{1, 2, \cdots, N-1}$

N pts. One Period

$$X(m) = X(m+kN) \quad \cdots (1)$$

Periodic Function,

Period = N

for $m=1$.

$$X(1) = x(0)e^{-j2\pi\frac{1\cdot 0}{N}} + x(1)e^{-j2\pi\frac{1\cdot 1}{N}} + \cdots + x(N-1)e^{-j2\pi\frac{1(N-1)}{N}}$$

$\vdots$

for $m=2, 3, \cdots$

$$X(N-1) = x(0)e^{-j2\pi\frac{(N-1)\cdot 0}{N}} + x(1)e^{-j2\pi\frac{(N-1)1}{N}} + \cdots + x(N-1)e^{-j2\pi\frac{(N-1)(N-1)}{N}}$$

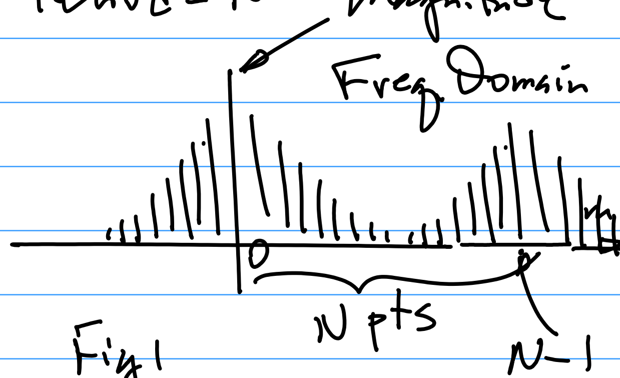
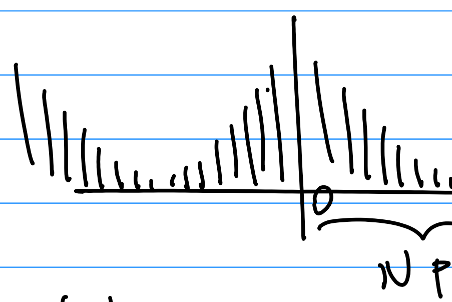


Fig 1

D.F.T.

$$\begin{bmatrix} X(0) \\ X(1) \\ X(2) \\ \vdots \\ X(N-1) \end{bmatrix} = \frac{1}{N} \begin{bmatrix} & & \\ & & \\ & & \end{bmatrix}_{N\times N} \begin{bmatrix} x(0) \\ x(1) \\ x(2) \\ \vdots \\ x(N-1) \end{bmatrix} \quad \cdots (5)$$



2. Right Hand input Digital Signal (Output from ADC) $x(n)$

Signal ↑ x, Time Index ↖ n

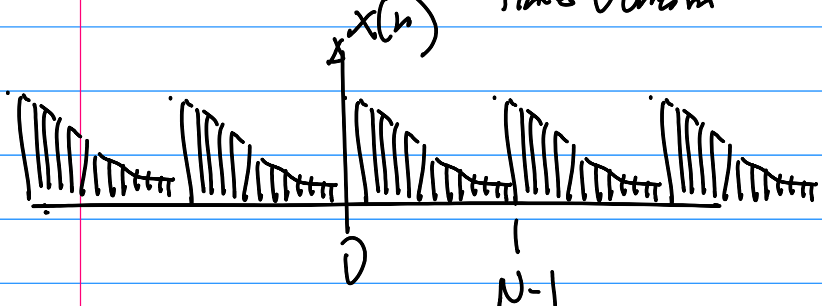
$$x(n) = x(n + pN)$$

$$X(m) = X(m + kN)$$

3. Denote Eqn (5) as follows.

$$x(n) = x(n + PN) \quad \ldots (2)$$

Periodic Function   Time Domain



$$\begin{pmatrix} X(0) \\ X(1) \\ X(2) \\ \vdots \\ X(N-1) \end{pmatrix} = \frac{1}{N} E_{N\times N} \begin{pmatrix} x(0) \\ x(1) \\ x(2) \\ \vdots \\ x(N-1) \end{pmatrix}$$

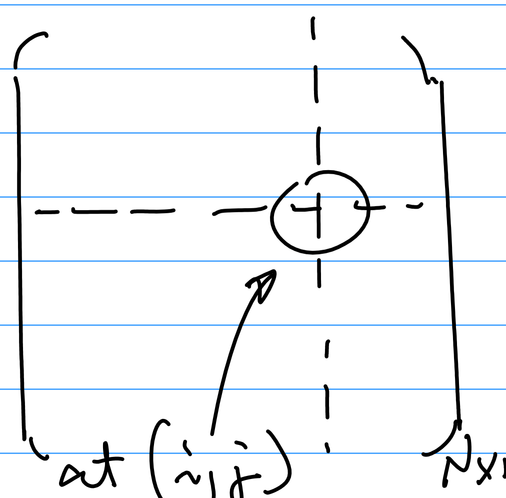
Note: (Optional) The process of Digitizing a function in One domain, either in Time Domain, or in Frequency Domain, will lead its Counterpart of the function become periodic function,

$$x(t) \xrightarrow{F.T.} X(f)$$

in time-Domain → $x(n)$ Digitized in Time

in frequency Domain → $X(m)$ Digitized (Conceptually) Freq.

$E_{N\times N} =$



$$e^{-j 2\pi \frac{i \cdot j}{N}} \quad \ldots (3)$$

Example: Find Entry of the $E_{N\times N}$ matrix at (2, 3) location, Suppose $N=4$.

From Eqn (3)

$$e^{-j2\pi\frac{i\cdot j}{N}}\Big|_{\substack{i=2\\j=3}} = ?$$

Euler Equation

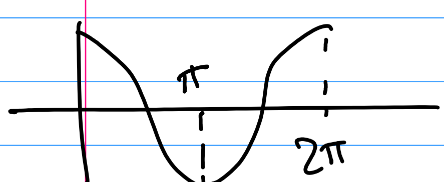
$$e^{-j2\pi\frac{mn}{N}} = \cos\left(2\pi\frac{mn}{N}\right) - j\sin\left(2\pi\frac{mn}{N}\right) \quad \cdots (4)$$

Based Eqn (4), & given Condition $i=2$, $j=3$,

$$e^{-j2\pi\frac{2\cdot3}{4}} = \cos\left(2\pi\frac{2\cdot3}{4}\right) - j\sin\left(2\pi\frac{2\cdot3}{4}\right)$$

$$= \cos(3\pi) - j\sin(3\pi) = -1 - j\cdot 0$$

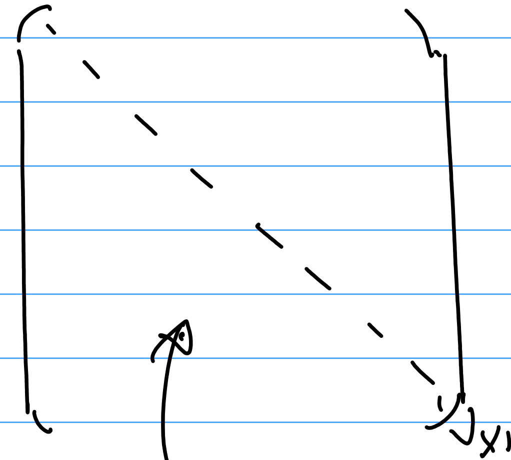
$$= -1$$



Note, This way, we can Evaluate Each of Every Entry of the matrix.

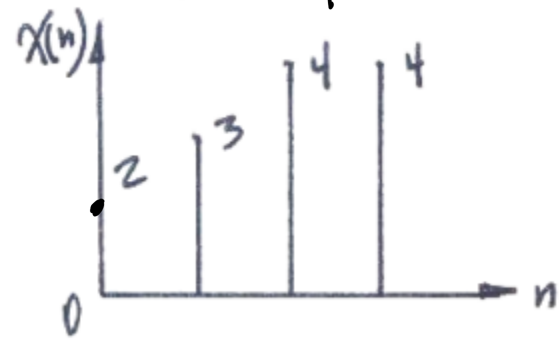
4. Entry for $E_{N\times N}$ is

$$e^{-j2\pi\frac{m\cdot n}{N}} = e^{-j2\pi\frac{n\cdot m}{N}}$$



Symmetric Along main Diagonal.

Example: Given $x(n)$ below, with $N=4$



Find/Compute its D.F.T

Sol From Eqn (5),

$$\begin{pmatrix} X(0) \\ X(1) \\ X(2) \\ \vdots \\ X(N-1) \end{pmatrix} = \frac{1}{N} E_{N\times N} \begin{pmatrix} x(0) \\ x(1) \\ x(2) \\ \vdots \\ x(N-1) \end{pmatrix}$$

$N=4$; $x(0)=2$, $x(1)=3$, $x(2)=4$, $x(3)=4$;

Then use Eqn (4*), we evaluate Each Entry.

$$\begin{array}{c|c} & n \rightarrow \\ \hline m \downarrow & \begin{bmatrix} \quad & \quad & \quad & \quad \\ & & & \\ & & & \\ & & & \end{bmatrix}_{N\times N} \end{array}$$

Visualize the following property as if you are standing at 1st Row & 1st Column position.

As you move top down, m index is increasing by 1 per row while n-index is unchanged

and, As you move from Left to Right, n index is increasing by 1 per colun while your m-Index is a Constant.

For 1st Row, 1st column Location $m=0, n=0$.

From Eqn (4*)

$$e^{-j2\pi\frac{mn}{N}} = e^{-j2\pi\frac{0\cdot 0}{N}} = e^{-j0} = 1$$

$$\begin{array}{c|c} & n \rightarrow \\ \hline m \downarrow & \begin{bmatrix} 1 & 1 & 1 & 1 \\ 1 & & & \\ & & & \\ & & & \end{bmatrix}_{N\times N} \end{array}$$

For 1st Row, 2nd Col.

$m=0$ $n=1$

$$e^{-j2\pi\frac{m\cdot n}{N}} = e^{-j2\pi\frac{0\cdot 1}{N}} = 1$$

For 1st Row, 3rd Col.

$$e^{-j2\pi\frac{m\cdot n}{N}} = e^{-j2\pi\frac{0\cdot 2}{N}} = 1$$

Now, for the 2nd Row, $m=1$

2nd Row, 1st col. $n=0$

$$e^{-j2\pi\frac{m\cdot n}{N}} = e^{-j2\pi\frac{1\cdot 0}{N}} = 1$$

2nd Row 2nd col, $n=1$

$$e^{-j2\pi\frac{m\cdot n}{N}} = e^{-j2\pi\frac{1\cdot 1}{4}} = e^{-j\pi/2} = -j$$

$i=1, j=2 \rightarrow$ Symmetric Entry.

$i=2, j=1$

$$e^{-j2\pi\frac{i\cdot j}{N}} = e^{-j2\pi\frac{1\cdot 2}{N}}$$

$$= e^{-j2\pi\frac{2\cdot 1}{N}}$$ (see github handout) Eqn. 3*

Now, Using Symmetric Property, Together with Euler Equation (4*) PP.48! we can build $E_{N\times N}$, for $N=4$.

Note: $N = 2^x \quad \ldots (1)$
for F.F.T (Fast Fourier Transform), the Above Condition has to hold good.

if Data Points from your ADC is not satisfied by Eqn (1), Then, pad "0"s to make it good.

Example (Continued from PP. 49)

Find D.F.T. (see Handout ONLine)

Now, Define Power Spectrum.

$$P(m) \triangleq \sqrt{Re^2[X(m)] + Im^2[X(m)]} \quad \ldots (2)$$

$P(m)$: Index freq.

$Re[X(m)]$: Real Part of the D.F.T.

$Im[X(m)]$: Imaginary Part of the D.F.T.

Physical meaning: Energy Distribution of a given Signal in Frequency Domain

Note: 1. D.C. Comp. $X(0)$, $m=0$

$$Re[X(1)] \stackrel{?}{=} -2/4, \quad Im[X(1)] = 1/4$$

$$X(m) = Re[X(m)] + j\, Im[X(m)]$$

$X(m)$: D.F.T.

from the Handout

$$Re[X(3)] = -2/4 \; ; \; Im[X(3)] = -1/4$$

2. Computation of $P(m)$ from $X(m)$

$$P(m)\Big|_{m=0} = \sqrt{Re^2[X(0)] + Im^2[X(0)]}$$

$$= \sqrt{3.25^2 + 0^2} = 3.25$$

$$P(1) = \frac{1}{4}\sqrt{(-2)^2 + 1^2} = \frac{1}{4}\sqrt{5}$$

Note:

$$P(m) = P(m+kN) \quad \ldots(3)$$

Note:

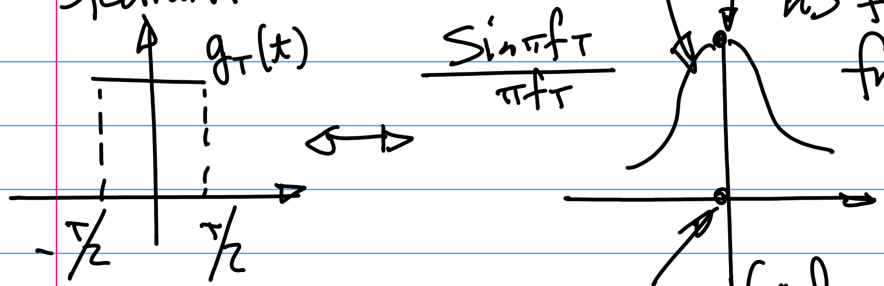
$$P(m) = P(-m) \quad \ldots(4)$$

Even function.

Common Power Spectrum is A Based Band Signal Power Spectrum.

DC. Comp.

Energy Distribution as function of frequency



Time Domain (Osc. to measure)

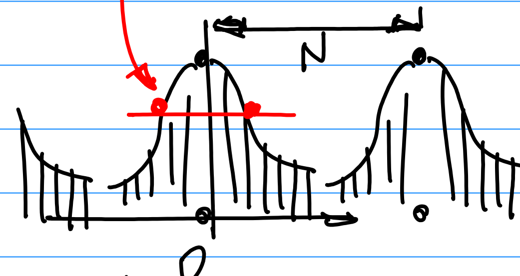
Fig 1.

(In freq. Domain) (Spectrum Analyzer)

Symmetric. "Mirror", Equal Even Function

Proof, Verification of Eqn (3)

Fig 3.



$$P(m) = \sqrt{Re^2[X(m)] + Im^2[X(m)]}$$

$$X(m) = X(m+kN)$$

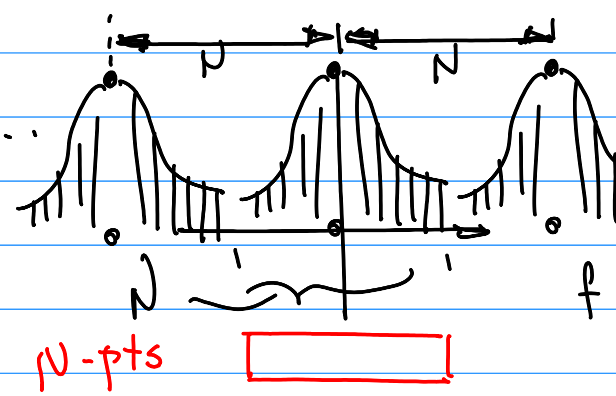
$$P(m+kN) = \sqrt{Re^2[X(m+kN)] + Im^2[X(m+kN)]}$$

$$= \sqrt{Re^2[X(m)] + Im^2[X(m)]}$$

May and (now).

Power Spectrum $\begin{cases} 1^\circ \text{ Even Func.} \\ 2^\circ \text{ Periodic Function.} \end{cases}$

Fig 4



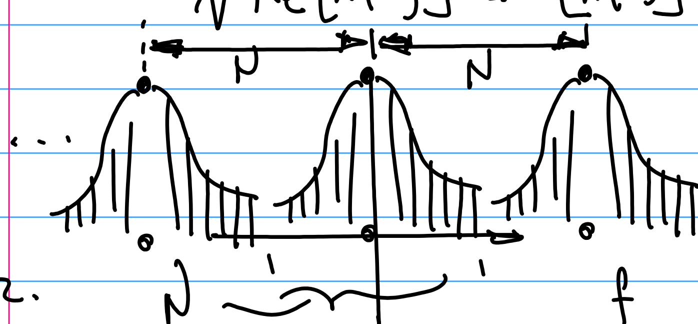


Fig 2.

1° "Mirror" wrt $m=0$ axis — One period

$[-\frac{N}{2}, \cdots 0], [0, \cdots, \frac{N}{2}]$

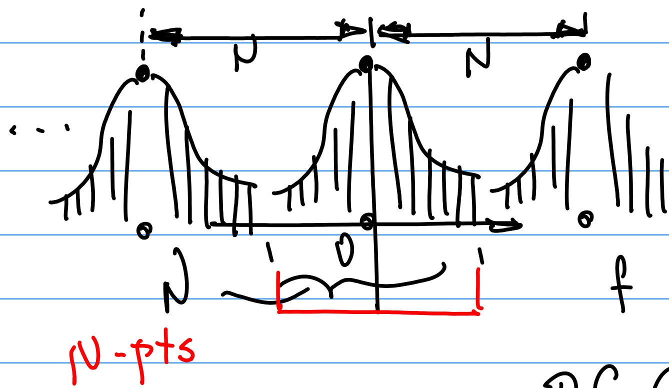


Fig5

D.C. Component, $P(m)_{m=0}$

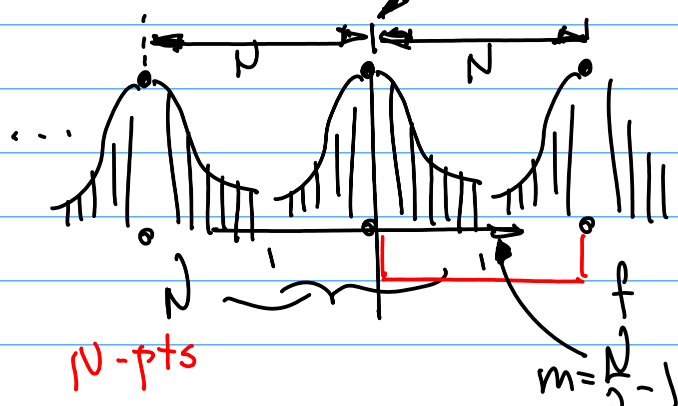


Fig6

2° One period, for $[0, N-1]$

a DC Component: $m=0$

b Highest Freq. Component

$m = N/2 - 1$; highest freq. Index

$X(\frac{N}{2}-1)$ highest frequency Componement

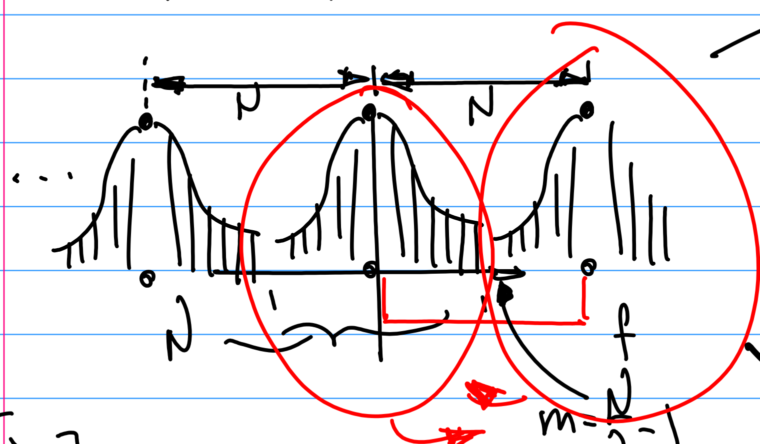
3° $\frac{1}{\Delta t_{Sampling}} = f_{Samping}$.

Marks the Distance Between Each Power Spectrum

higher $f_{sampling}$ — Further Apart

Fig8

higher Freq. Comp.



lower Sampling — Sampling Freq. $\frac{1}{\Delta t}$ Fig9.

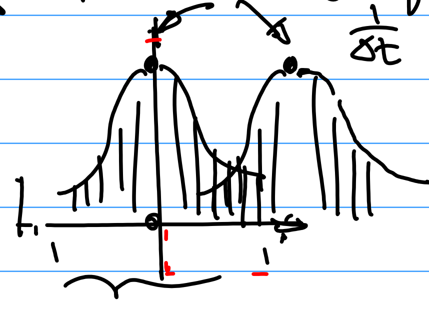


Fig.7

"Aliasing"

Distortion Due to higher Freq. Comp.

Added up from insufficient Sampling Freq.

$f_{sampling} \geq 2 f_{max}$ ... (1)

Total N points

Energy Index $I_{\Sigma} = \sum_{m=0}^{N-1} P(m)$ ... (2)

Entire Energy;

K+1 Points

$I_D = \sum_{m=0}^{K} P(m)$ ... (3)

Desired (user defined)

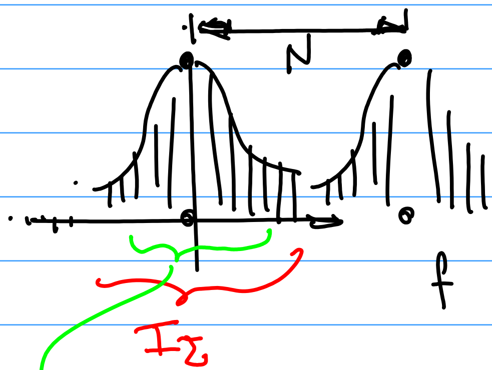


Fig10

I_D : K+1 points
Some higher Freq. Comp.
Excluded to Relax
the "Alisaing".

$$\eta = \frac{I_D}{I_\Sigma} = \frac{\sum_{m=0}^{K} P(m)}{\sum_{m=0}^{N-1} P(m)} \quad \dots (4)$$

For Example $\eta = 90\%$.

Note (Conclusion): When Index $\eta \downarrow$ for a fixed K, that is the indication of the fact $f_{sampling}$ is too Small, and Caused no Energy distribution at higher freq. range distortion, e.g. Alisaing.

To fix it: Increase the Sampling rate, $f_{sampling}$.

In the Project:

1. Change Settings of the Potentialmeter CKT
2. ADC output Data $x(n)$ Captured $\{x(n) \mid n = 0, 1, \dots, 1023\}$ → 3. Compute D.F.T $X(m)$, $\{X(m) \mid m = 0, 1, 2, \dots, 1023\}$ By F.F.T.
4. Compute $\{P(m) \mid m = 0, 1, 2, \dots, 1023\}$

May 4 (Wed)

(5) Compute $I_\Sigma = \sum_{m=0}^{N-1} P(m)$, and

$I_D = \sum_{m=0}^{K} P(m)$, where ... (5)

K : freq. Index for a Bandwidth,

Example: $K = 0.8\left(\frac{N}{2} - 1\right)$ ... (6)

Based on Certain Design Requirements, it can be different Number. like 0.2 for Example

Entire Freq. Range

(6) $\eta = I_D / I_\Sigma$ ... (7)

Based Your Data (Power Spectrum Result) if $\eta <$ Threshold (for Example 80% or 90% by Customer)

Then, the Data is No good. Increase $f_{Sampling}$ to Resolve it.

May 4th (Wed)

Show & Tell of the Prototype System is mandatory. This Lecture & Next for the Additional Show + Tell.

$$I_\Sigma = \sum_{m=0}^{N-1} P(m) = 2\sum_{m=0}^{N/2} P(m)$$

Note: Example on github 1-2020S-APL6, ... "missing coefficient "2" please verify.

Example: Evaluating ARM-11 Target Board.

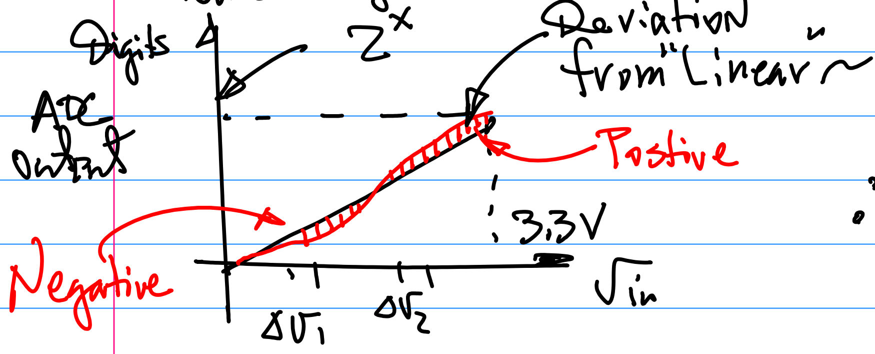
Note: Show + Tell of the Prototype System is mandatory, Timely Demo is required Without Adequate Demo, the Entire Course Performance will be Negatively Impacted. (By Next Monday)

1. CPU Datasheet.
   Base Concept.
   Special Purpose Registers
   Formula to Compute $f_{Sampling}$. Δt_{Sample}.

Chapter 3a ADC

a. 10 or 12 bit Resolution

b. NonLinearity



$\Delta V \sim \alpha \Delta d$

Fig.1

$V_{in}=0$, $ADC=0$

(V_i, ADC_i) for $(0.23, 33), \ldots$

Question: How to generate ADC Characteristic Curve? 10 pair points to plot them.

How Do you correct the Non-Linear Curve from ADC?

Red NonLinear $f_r(x)$

Compensation function $f_{Comp}(x)$

$$f_r(x) + f_{Comp}(x) = ax + b \quad \ldots (1)$$

$b = 0$ (Calibration)

$$f_r(x) + f_{Comp}(x) = ax \quad \ldots (2)$$

$$a = \frac{2^x}{\Delta V_{max}} = \frac{2^{10}}{3.3}$$

$x = 10$ bits
3.3 full Range

$$= 2^{10}/3.3$$

$$\therefore f_{Comp}(x) = ax - f_r(x) \quad \ldots (3)$$

c. Non-Linearity $\leq \pm 2$LSB

Example for 10 bits ADC

$$2^x \Big|_{x=10} = 1024$$

$X=10$ Bits

1024 Levels.

Find Deviation for 1 LSB

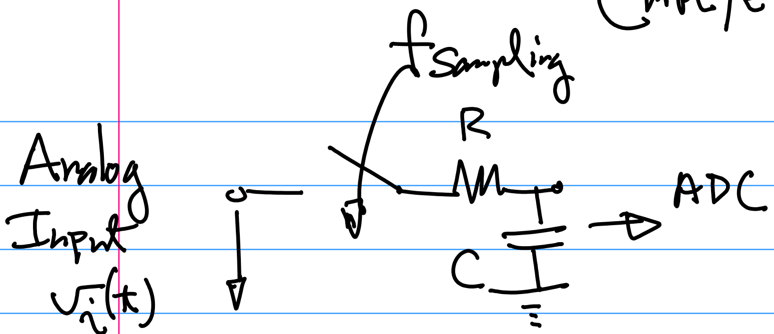
$$X_9 X_8 X_7 \ldots X_2 X_1 \underbrace{X_0}_{LSB}$$

$\Delta V = \frac{3.3}{1024}$ for 1 LSB (+)

$2\Delta V$ for 1 LSB (±)

for ±2LSB: $2\Delta V = 2 \cdot \frac{3.3}{512}$

d. Sample and Hold CKT.



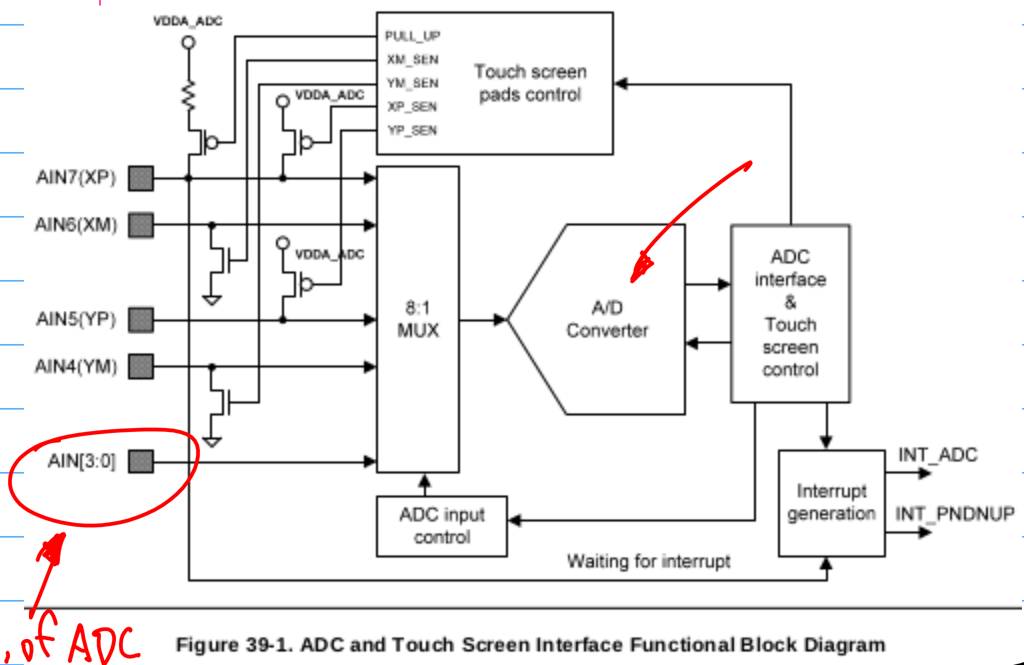


Figure 39-1. ADC and Touch Screen Interface Functional Block Diagram

Nyquest Theorem

Example: $f_{Sampling} \triangleq \dfrac{f_{PCLK}}{Pres+1}$ ...(4)

$\triangleq$ System CLK → Peripheral CLK → ADC CLK

39.4.1 A/D CONVERSION TIME

When the PCLK frequency is 50MHz and the prescaler value is 49, total 10-bit or 12-bit conversion time is as follows.

A/D converter freq. = 50MHz/(49+1) = 1MHz ← $f_{sampling}$

Conversion time = 1/(1MHz / (5cycles)) = 1/200KHz =5 us

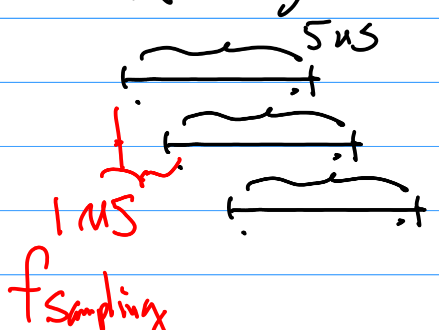
$\triangleq$ "Pras" Prescaler, Special Purpose Register

↑ 5x (Times) the Sampling Δt

$\Delta t_{Sampling} = 1/f_{Sampling}$

$= \dfrac{1}{1\times10^6} = 1\times10^{-6}$

$= 1\ \mu s$



CmpE/EE242

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Example: S.P.R.

Final May 21 (Friday)
1215 — 1430

39.6 ADC AND TOUCH SCREEN INTERFACE SPECIAL REGISTERS

39.6.1 REGISTER MAP

Naming Convention: Prefix + Root
ADC CON

Register	Address	R/W	Description
ADCCON	0x7E00_B000	R/W	ADC Control Register
ADCTSC	0x7E00_B004	R/W	ADC Touch Screen Control Register
ADCDLY	0x7E00_B008	R/W	ADC Start or Interval Delay Register
ADCDAT0	0x7E00_B00C	R	ADC Conversion Data Register
ADCDAT1	0x7E00_B010	R	ADC Conversion Data Register
ADCUPDN	0x7E00_B014	R/W	Stylus Up or Down Interrupt Register
ADCCLRINT	0x7E00_B018	W	Clear ADC Interrupt
Reserved	0x7E00_B01C	-	reserved
ADCCLRINTPNDNUP	0x7E00_B020	W	Clear Pen Down/Up Interrupt

Example: Required

6410X_UM ADC AND TOUCH S

39.6.2 ADC CONTROL REGISTER (ADCCON)

Register	Address	R/W	Description
ADCCON	0x7E00B000	R/W	ADC Control Register

ADCCON	Bit	Description
RESSEL	[16]	A/D converter resolution selection 0 = 10-bit A/D conversion 1 = 12-bit A/D conversion
ECFLG	[15]	End of conversion flag(Read only) 0 = A/D conversion in process 1 = End of A/D conversion
PRSCEN	[14]	A/D converter prescaler enable 0 = Disable 1 = Enable

Final: May 21st (Friday) 1215-1430

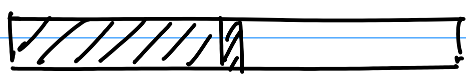
Team Presentation 7 min.

- a PPT 3~5 Slides.
- b Readme.txt Document
- c 5±1 min. Presentation.
  Q&A Session
- d Source Code Header
  - Program Name
  - Coded by
  - Ref.
  - Status: Debug / Tested
  - Version 0x1.0
  - Note:

Submission: All Coding, Report have to be individual/Independent. No material can be shared.

- e Presentation Date May 17th In Class.

Example: 39-7 ADCCON Table



ADCCON[16:0]

ADCCON[16]=1 for 12 bit Quantization

ADCCON[14]=1 to Enable Prescaler

ADCCON[13:6] Prescaler, See Eqn(4)

$$f_{Sampling} \triangleq \frac{f_{PCLK}}{Pres+1} \quad \ldots(4)$$ pp.56

Example: Design

$f_{Sampling} = ?$

① Find f_{max} of the Signal

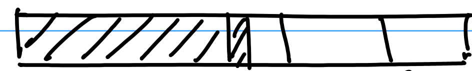
② $f_{Sampling} \geq 2 f_{max}$

Nyquist Theorem

③ Hence $f_{Sampling} = \dfrac{f_{PCLK}}{Pres+1}$

f_{PCLK} is given; find Prescaler = ?

Suppose, Prescaler = 75 (Digits)



ADCCON[13:6] = (Hex)

Note: ADCCON[13:6] ~ [5,255]

ADCCON[5:3] = 001 for AIN1 etc.

Requirements: Binary Pattern ⇄ Tech Spec.

ADCDAT for 10 bits & 12 bits Data.

ADCDAT[9:0] for 10 bits

ADCDAT[11:0] for 12 bits

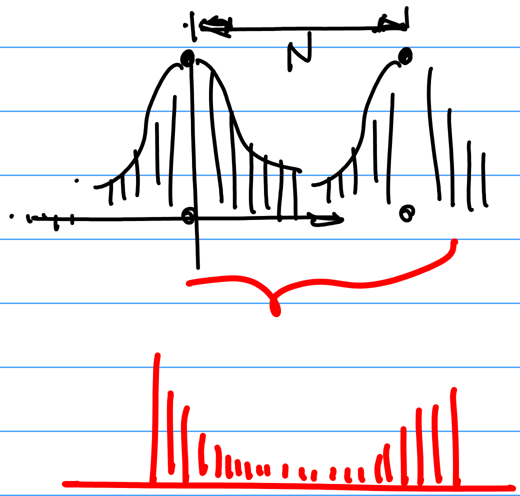


Fig 1.

a Signal (Low Pass) w/o modulation

b Finite Energy

c Even function, d Periodic Function

FFT → Save Data in a File → Open the Data File By .xls → plot