GPU Implementation of Data-Aided Equalizers

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ABSTRACT

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Multipath is one of the dominant causes for link loss in aeronautical telemetry. Equalizers have been studied to combat multipath interference in aeronautical telemetry. Blind Constant Modulus Algorithm (CMA) equalizers are currently being used on SOQPSK-TG. The Preamble Assisted Equalization (PAQ) has been funded by the Air Force to study data-aided equalizers on SOQPSK-TG. PAQ compares side by side no equalization, data-aided zero forcing equalization, data-aided MMSE equalization, data-aided initialized CMA equalization, data-aided frequency domain equalization, and blind CMA equalization. An real time experimental test setup has been assembled including an RF receiver for data acquisition, FPGA for hardware interfacing and buffering, GPUs for signal processing, spectrum analyzer for viewing multipath events, and an 8 channel bit error rate tester to compare equalization performance. Lab tests were done with channel and noise emulators. Flight tests were conducted in March 2016 and June 2016 at Edwards Air Force Base to test the equalizers on live signals. The test setup achieved a 10Mbps throughput with a 6 second delay. Counter intuitive to the simulation results, the flight tests at Edwards AFB in March and June showed blind equalization is superior to data-aided equalization. Lab tests revealed some types of multipath caused timing loops in the RF receiver to produce garbage samples. Data-aided equalizers based on data-aided channel estimation leads to high bit error rates. A new experimental setup is been proposed, replacing the RF receiver with a RF data acquisition card. The data acquisition card will always provide good samples because the card has no timing loops, regardless of severe multipath.

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Chapter 1

Equalizer Equations

1.1 Overview

There are 3 different kinds of equalizers I run 1. the solving ones!!! They are equations like Ax=b where I have A and b but I need x 2. the initialized then iterative ones. CMA is initialized with MMSE then runs as many times a possible 3. the multiply ones! the FDEs are a simple multiply in the frequency domain

1.2 Equations

1.2.1 The Solving Equalizers

The Zero-Forcing Equalizer

The ZF equalizer was studied in the PAQ Phase 1 Final Report in equation 324

$$\mathbf{c}_{\text{ZF}} = (\mathbf{H}^{\dagger}\mathbf{H})^{-1}\mathbf{H}^{\dagger}\mathbf{u}_{n_0} \tag{1.1}$$

where $\mathbf{c}_{\text{ZF}}$ is a $L_{eq} \times 1$ vector of equalizer coefficients computed to invert the channel estimate $\mathbf{h}$. The channel estimate is used to build the $L_{eq} + N_1 + N_2 \times L_{eq}$ convolution matrix

$$\mathbf{H} = \begin{bmatrix} h(-N_1) & & & \\ h(-N_1+1) & h(-N_1) & & \\ \vdots & \vdots & \ddots & \\ h(N_2) & h(N_2-1) & & h(-N_1) \\ & h(N_2) & & h(-N_1+1) \\ & & & \vdots \\ & & & h(N_2) \end{bmatrix}. \tag{1.2}$$

and $\mathbf{u}_{n_0}$ is the desired channel impulse response centered on $n0 = N_1 + L_1 + 1$

$$\mathbf{u}_{n_0} = \begin{bmatrix} 0 \\ \vdots \\ 0 \\ 1 \\ 0 \\ \vdots \\ 0 \end{bmatrix} \begin{matrix} \left.\begin{matrix} \\ \\ \\ \end{matrix}\right\} n_0 - 1 \text{ zeros} \\ \\ \left.\begin{matrix} \\ \\ \\ \end{matrix}\right\} N_1 + N_2 + L_1 + L_2 - n_0 + 1 \text{ zeros} \end{matrix} . \tag{1.3}$$

The computation of the coefficients in Equation (1.1) can be simplified in a couple of ways: First the matrix multiplication of $\mathbf{H}^\dagger$ and $\mathbf{H}$ is the autocorrelation matrix of the channel

$$\mathbf{R}_h = \mathbf{H}^\dagger \mathbf{H} = \begin{bmatrix} r_h(0) & r_h^*(1) & \cdots & r_h^*(L_{eq}-1) \\ r_h(1) & r_h(0) & \cdots & r_h^*(L_{eq}-2) \\ \vdots & \vdots & \ddots & \\ r_h(L_{eq}-1) & r_h(L_{eq}-2) & \cdots & r_h(0) \end{bmatrix} \tag{1.4}$$

where

$$r_h(k) = \sum_{n=-N_1}^{N_2} h(n)h^*(n-k). \tag{1.5}$$

Second the matrix vector multiplication of $\mathbf{H}^\dagger$ and $\mathbf{u}_{n_0}$ is simply the n_0th row of $\mathbf{H}^\dagger$ or the conjugated n_0th column of $\mathbf{H}$. A new vector $\mathbf{h}_{n_0}$ is defined by

$$\mathbf{h}_{n_0} = \mathbf{H}^\dagger \mathbf{u}_{n_0} = \begin{bmatrix} h(L_1) \\ \vdots \\ h(0) \\ \vdots \\ h(-L_2) \end{bmatrix} . \tag{1.6}$$

Replacing the matrix multiplication $\mathbf{H}^\dagger\mathbf{H}$ and $\mathbf{H}^\dagger\mathbf{u}_{n_0}$ simplifies Equation (1.1) to

$$\mathbf{c}_{\text{ZF}} = \mathbf{R}_h^{-1}\mathbf{h}_{n_0}. \tag{1.7}$$

Computing the inverse of $\mathbf{R}_h$ is computationally heavy because an inverse is an N^3 operation. To avoid an inverse, $\mathbf{R}_h$ is moved to the left side and $\mathbf{c}_{\text{ZF}}$ is found by solving a system of linear equations. Note that $r_h(k)$ only has support on $-L_{ch} \leq k \leq L_{ch}$ making $\mathbf{R}_h$ sparse or $\%63$ zeros. The sparseness of $\mathbf{R}_h$ can be leveraged to reduce computation drastically. The Zero-Forcing Equalizer coefficients are computed by solving

$$\mathbf{R}_h\mathbf{c}_{\text{ZF}} = \mathbf{h}_{n_0}. \tag{1.8}$$

MMSE Equalizer

The MMSE equalizer was studied in the PAQ Phase 1 Final Report in equation 330.

$$\mathbf{c}_{MMSE} = \left[\mathbf{G}\mathbf{G}^\dagger + \frac{\sigma_w^2}{\sigma_s^2}\mathbf{I}_{L_1+L_2+1}\right]\mathbf{g}^\dagger \tag{1.9}$$

where

$$\mathbf{G} = \begin{bmatrix} h(N_2) & \cdots & h(-N_1) & & & \\ & h(N_2) & \cdots & h(-N_1) & & \\ & & \ddots & & \ddots & \\ & & & h(N_2) & \cdots & h(-N_1) \end{bmatrix} \tag{1.10}$$

and

$$\mathbf{g} = \begin{bmatrix} h(L_1) \cdots h(-L_2) \end{bmatrix}. \tag{1.11}$$

The matrix multiplication $\mathbf{G}\mathbf{G}^\dagger$ is the same autocorrelation matrix $\mathbf{R}_h$ as Equation (1.4). The vector $\mathbf{g}^\dagger$ is also the same vector as $\mathbf{h}_{n_0}$. The signal-to-noise ratio estimate $\frac{1}{2\hat{\sigma_w^2}}$ is substituted in for the fraction $\frac{\sigma_w^2}{\sigma_s^2}$ using Equation 333 Rice's report. Equation (1.9) can be reformulated to

$$\left[\mathbf{R}_h + \frac{1}{2\hat{\sigma_w^2}}\mathbf{I}_{L_1+L_2+1}\right]\mathbf{c}_{\text{MMSE}} = \mathbf{h}_{n_0}. \tag{1.12}$$

The MMSE Equalizer coefficients are solved for in a similar fashion to Zero-Forcing is in Equation (1.8). The only difference between Equation (1.12) and (1.8) is the noise variance is added down the diagonal of $\mathbf{R}_h$. The matrix $\mathbf{R}_{hw}$ is defined to make the computation of the MMSE Equalizer coefficients the same as the Zero-Forcing Equalizer coefficients by adding the noise variance to the diagonal of $\mathbf{R}_h$

$$\mathbf{R}_{hw} = \mathbf{H}^{\dagger}\mathbf{H} = \begin{bmatrix} r_h(0) + \frac{1}{2\hat{\sigma_w^2}} & r_h^*(1) & \cdots & r_h^*(L_{eq}-1) \\ r_h(1) & r_h(0) + \frac{1}{2\hat{\sigma_w^2}} & \cdots & r_h^*(L_{eq}-2) \\ \vdots & \vdots & \ddots & \\ r_h(L_{eq}-1) & r_h(L_{eq}-2) & \cdots & r_h(0) + \frac{1}{2\hat{\sigma_w^2}} \end{bmatrix}. \tag{1.13}$$

The MMSE Equalizer coefficients are computed by solving

$$\mathbf{R}_{hw}\mathbf{c}_{\text{MMSE}} = \mathbf{h}_{n_0}. \tag{1.14}$$

1.2.2 The Iterative Equalizer

The Constant Modulus Algorithm

CMA uses a steepest decent algorithm.

$$\mathbf{c}_{b+1} = \mathbf{c}_b - \mu \nabla \mathbf{J} \tag{1.15}$$

The vector $\mathbf{J}$ is the cost function and ∇J is the cost function gradient defined in the PAQ report 352 by

$$\nabla J = \frac{2}{L_{pkt}} \sum_{n=0}^{L_{pkt}-1} \Big[y(n)y^*(n) - R_2 \Big] \, y(n)\mathbf{r}^*(n). \tag{1.16}$$

where

$$\mathbf{r}(n) = \begin{bmatrix} r(n+L_1) \\ \vdots \\ r(n) \\ \vdots \\ r(n-L_2) \end{bmatrix}. \tag{1.17}$$

This means ∇J is of the form

$$\nabla J = \begin{bmatrix} \nabla J(-L_1) \\ \vdots \\ \nabla J(0) \\ \vdots \\ \nabla J(L_2) \end{bmatrix}. \tag{1.18}$$

To Leverage computational efficiency of FFT, re-express the elements of ∇J as a convolution.

To begin define

$$z(n) = 2 \Big[y(n)y^*(n) - R_2 \Big] \, y(n) \tag{1.19}$$

so that ∇J may be expressed as

$$\nabla J = \frac{z(0)}{L_{pkt}} \begin{bmatrix} r^*(L_1) \\ \vdots \\ r^*(0) \\ \vdots \\ r^*(L_2) \end{bmatrix} + \frac{z(1)}{L_{pkt}} \begin{bmatrix} r^*(1+L_1) \\ \vdots \\ r^*(1) \\ \vdots \\ r^*(1-L_2) \end{bmatrix} + \cdots \frac{z(L_{pkt}-1)}{L_{pkt}} \begin{bmatrix} r^*(L_{pkt}-1+L_1) \\ \vdots \\ r^*(L_{pkt}-1) \\ \vdots \\ r^*(L_{pkt}-1-L_2) \end{bmatrix}. \quad (1.20)$$

The kth value of ∇J is

$$\nabla J(k) = \frac{1}{L_{pkt}} \sum_{m=0}^{L_{pkt}-1} z(m) r^*(m-k), \quad -L_1 \leq k \leq L_2. \quad (1.21)$$

The summation almost looks like a convolution. To put the summation in convolution form, define

$$\rho(n) = r^*(n). \quad (1.22)$$

Now

$$\nabla J(k) = \frac{1}{L_{pkt}} \sum_{m=0}^{L_{pkt}-1} z(m) \rho(k-m). \quad (1.23)$$

Because $z(n)$ has support on $0 \leq n \leq L_{pkt}-1$ and $\rho(n)$ has support on $-L_{pkt}+1 \leq n \leq 0$, the result of the convolution sum $b(n)$ has support on $-L_{pkt}+1 \leq n \leq L_{pkt}-1$. Putting all the pieces together, we have

$$\begin{aligned} b(n) &= \sum_{m=0}^{L_{pkt}-1} z(m)\rho(n-m) \\ &= \sum_{m=0}^{L_{pkt}-1} z(mr^*(m-n) \end{aligned} \quad (1.24)$$

Comparing Equation (1.23) and (1.24) shows that

$$\nabla J(k) = \frac{1}{L_{pkt}} b(k), \quad -L_1 \leq k \leq L_2. \quad (1.25)$$

The values of interest are shown in Figure Foo!!!!(c)

This suggest the following algorithm for computing the gradient vector ∇J: Matlab Code!!!