

Moving Target Indicator

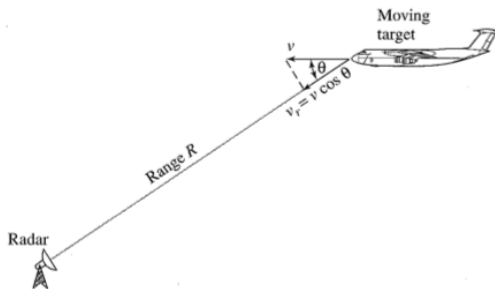
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IIT Bombay, Powai

April 25, 2014

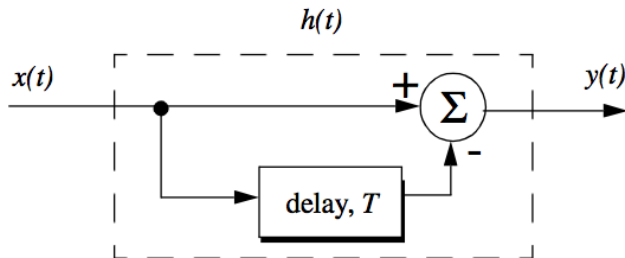
Moving Target Indicator

- ▶ mode of operation of radar
- ▶ makes use of doppler effect



Source: Merrill I. Skolnik. *Introduction to Radar Systems*. McGraw-Hill, 2001.

Single Delay Line Canceler



Source: Bassem R. Mahafza. *Radar Systems Analysis and Design Using MATLAB[®]*. Chapman & Hall/CRC, 2000.

Single Delay Line Canceler

$$h(t) = \delta(t) - \delta(t - T)$$

$$H(\omega) = 1 - e^{-j\omega T}$$

$$\begin{aligned}|H(\omega)|^2 &= H(\omega)H^*(\omega) \\ &= (1 - e^{-j\omega T})(1 - e^{j\omega T}) \\ &= 2(1 - \cos\omega T) \\ &= 4(\sin(\omega T/2))^2\end{aligned}$$

Double Delay Line Canceler

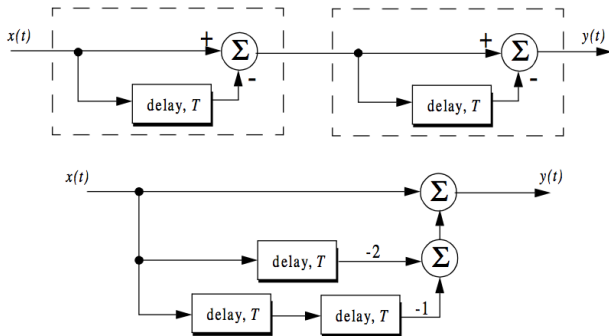


Figure : Two configurations for a double delay line canceler

Double Delay Line Canceler

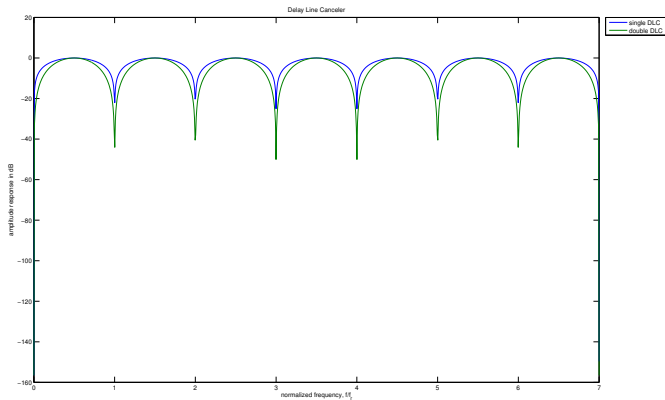
$$h(t) = \delta(t) - 2\delta(t - T) + \delta(t - 2T)$$

$$|H(\omega)|^2 = |H_1(\omega)|^2 |H_1(\omega)|^2$$

$$\text{where } |H_1(\omega)|^2 = 4(\sin(\omega T/2))^2$$

$$|H(\omega)|^2 = 16 \left(\sin \left(\omega \frac{T}{2} \right) \right)^4$$

Delay Line Canceler



Delay Lines with Feedback

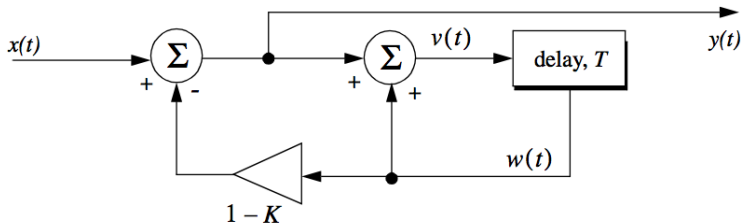
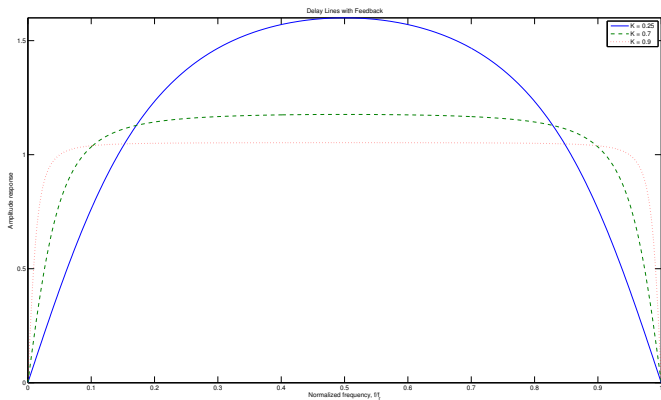


Figure : MTI recursive filter

Delay Lines with Feedback

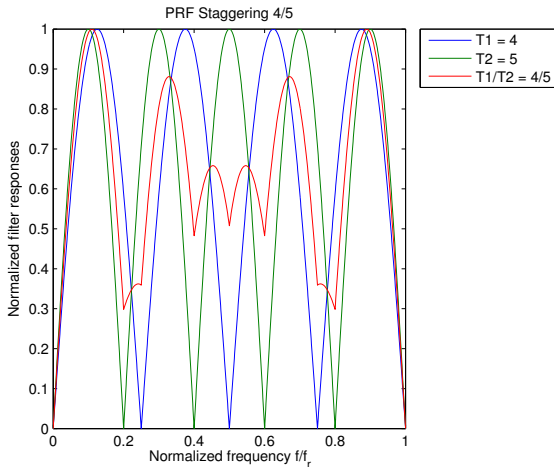
$$\begin{aligned}H(z) &= \frac{1 - z^{-1}}{1 - Kz^{-1}} \\|H(z)|^2 &= \frac{(1 - z^{-1})(1 - z)}{(1 - Kz^{-1})(1 - Kz)} \\&= \frac{2 - (z + z^{-1})}{(1 + K^2) - K(z + z^{-1})} \\|H(e^{j\omega T})|^2 &= \frac{2(1 - \cos\omega T)}{(1 + K^2) - 2K\cos(\omega T)}\end{aligned}$$

Delay Lines with Feedback



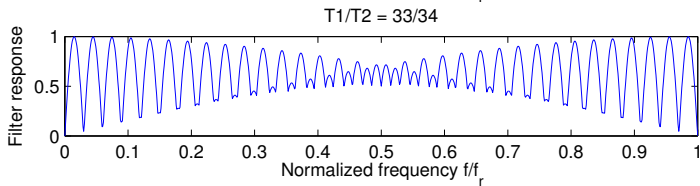
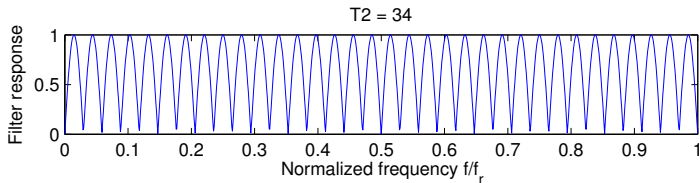
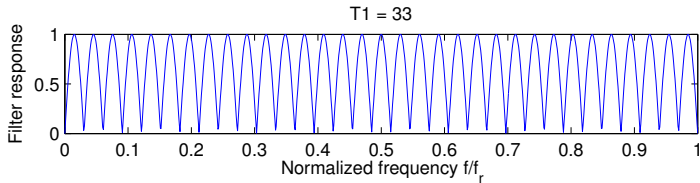
Source: Bassem R. Mahafza. *Radar Systems Analysis and Design Using MATLAB[®]*. Chapman & Hall/CRC, 2000.

PRF Staggering 4/5

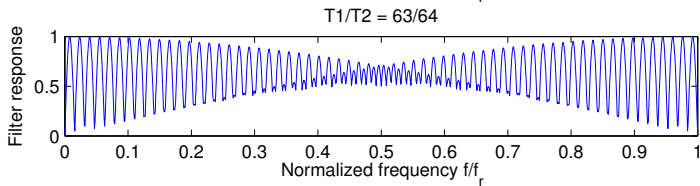
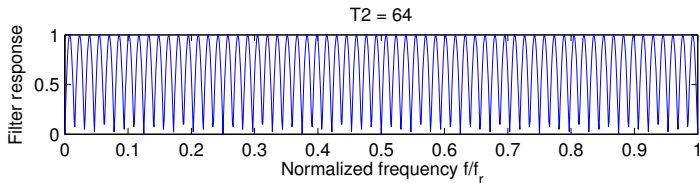
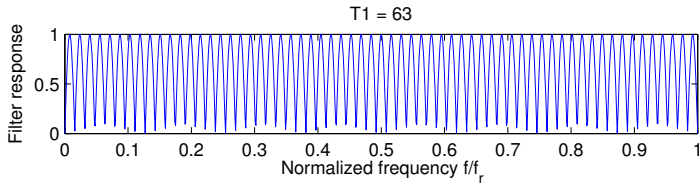


Source: Bassem R. Mahafza. *Radar Systems Analysis and Design Using MATLAB®*. Chapman & Hall/CRC, 2000.

PRF Staggering 33/34



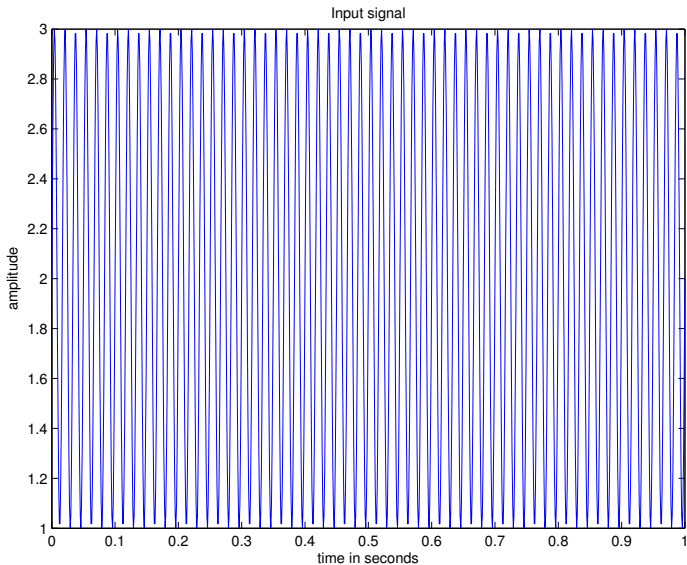
PRF Staggering 63/64



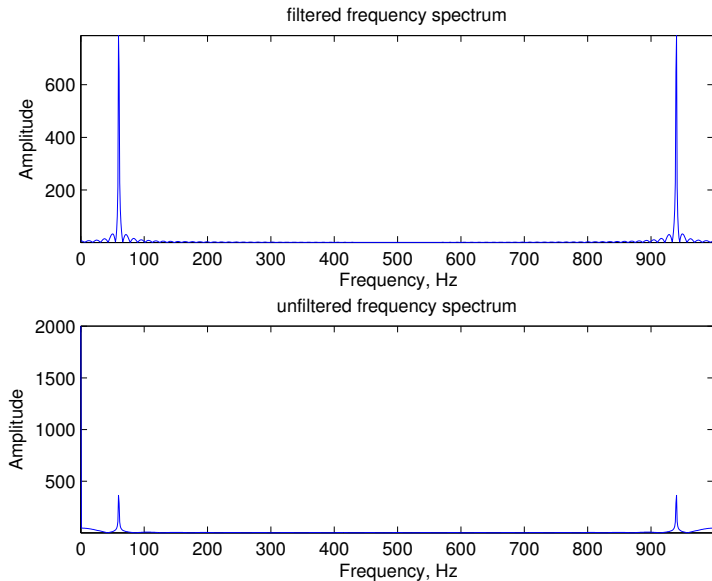
First staggered blind speed

$$\frac{n_1}{T_1} = \frac{n_2}{T_2} = \dots = \frac{n_N}{T_N}$$
$$v_{blind} = \frac{n_1 + n_2 + \dots + n_N}{N} v_{blind1}$$

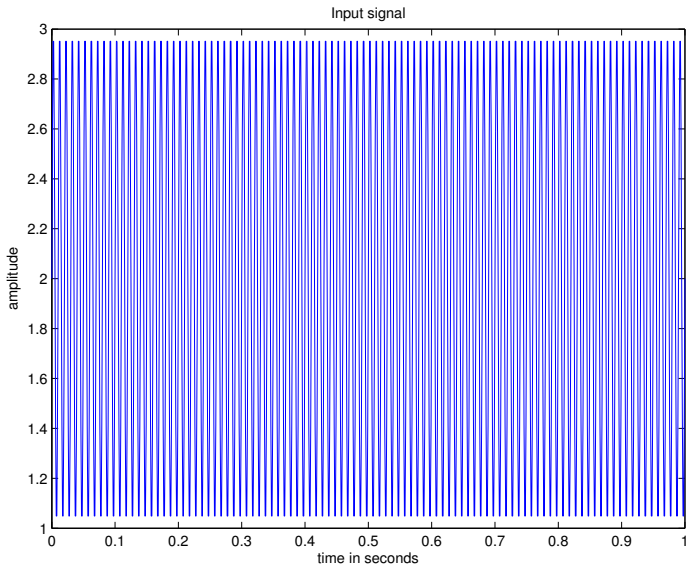
60Hz input



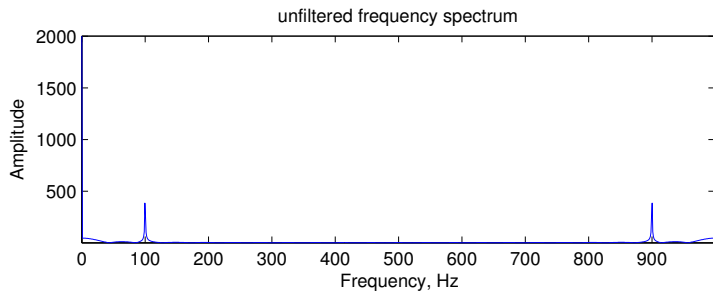
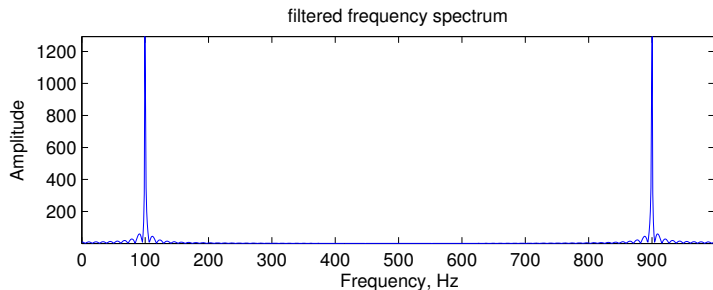
Filtered spectrum of 60Hz input



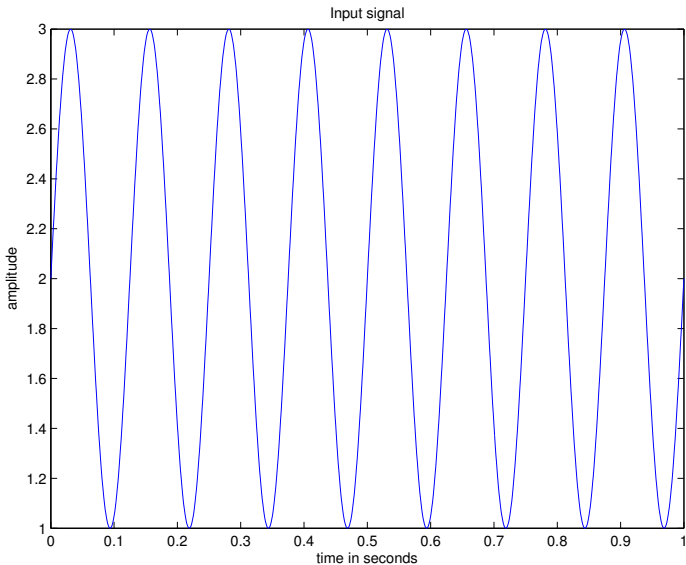
100Hz input



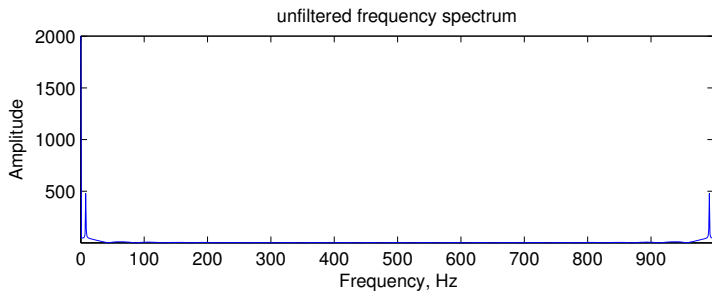
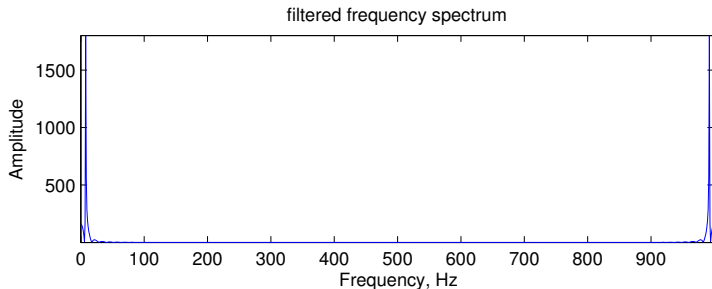
Filtered spectrum of 100Hz input



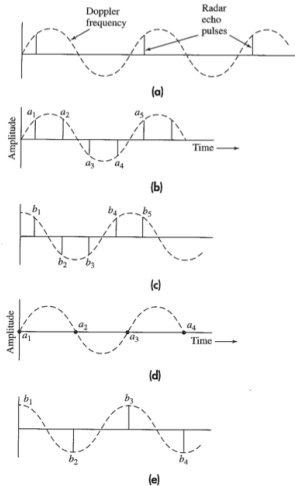
1008Hz input



Filtered spectrum of 1008Hz input

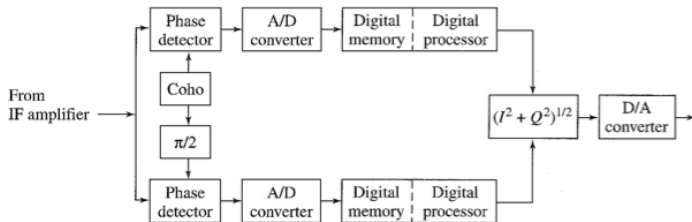


Digital MTI (I and Q channels)



Source: Merrill I. Skolnik. *Introduction to Radar Systems*. McGraw-Hill, 2001.

Digital MTI Processor



Source: Merrill I. Skolnik. *Introduction to Radar Systems*. McGraw-Hill, 2001.

References

- ▶ Merrill I. Skolnik. *Introduction to Radar Systems*. McGraw-Hill, 2001.
- ▶ Bassem R. Mahafza. *Radar Systems Analysis and Design Using MATLAB®*. Chapman & Hall/CRC, 2000.

Thanks