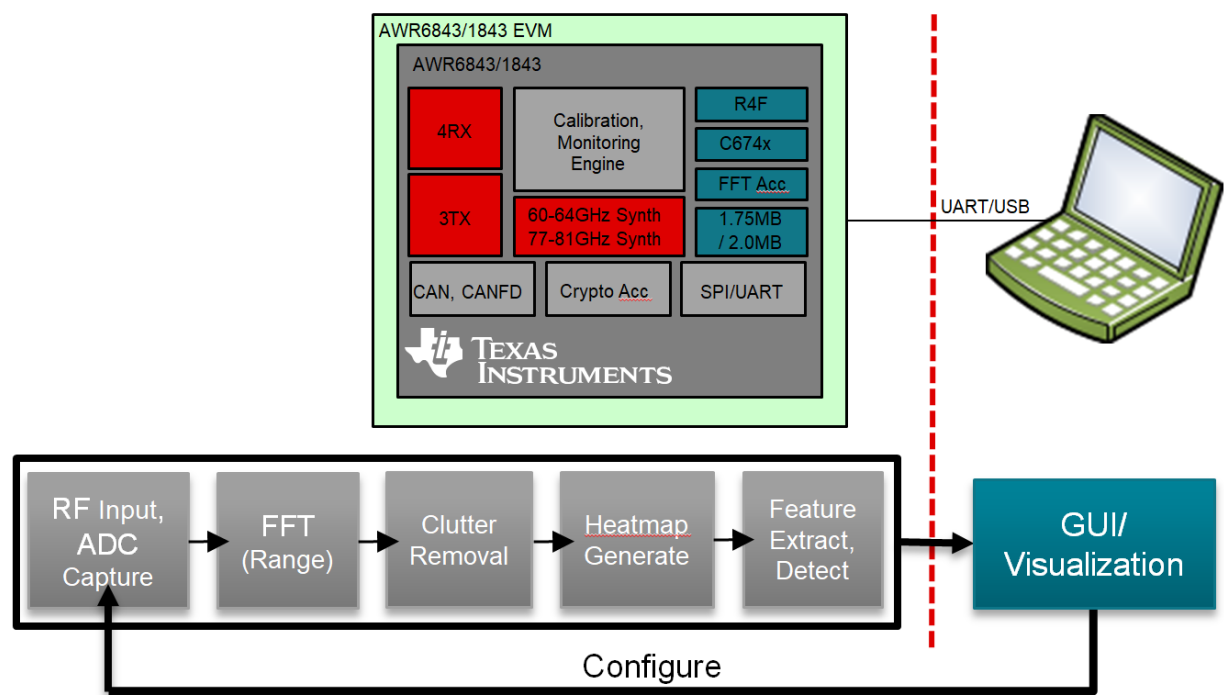


# Overview

This lab demonstrates the use of TI mmWave sensors to detect people and animals in pre-defined zones of coverage. Using TI 60GHz AWR6843, and 77GHz AWR1843 and AWR1642 mmWave devices, algorithms run onboard the single-chip device to create an Range-Azimuth heatmap, then extract features and detections from the heatmap. Chirp configurations are selected to detect slight movements (like breathing) with a high degree of accuracy. Two use cases are supported - Vehicle Occupancy Detection (VOD) and Child Presence Detection (CPD).



This version features several recent updates:

- The demo now runs in one of three modes: Operational, Zone Tuning, Data Collection.
- The GUI supports different displays for each mode, and multiple operational displays.
- The demo supports the concept of secondary zones, which are used to help primary zone decisions.
- An Arc Removal algorithm, with automatic noise-floor command generation.
- An improved 32-bit clutter removal algorithm that will not overflow with strong targets.
- A new "max 5x5" method of determining zone power.
- Occupant position is now output in the decision vector.
- A configurable heatmap "smoothing" function.

# Quickstart

The quickstart contains:

- Precompiled binaries for flashing the device using Uniflash
- Visualizer as .exe

## 1. Hardware and Software Requirements

### Hardware

Item	Details
Device	AWR6843 EVM, AWR1843 EVM or AWR1642 EVM

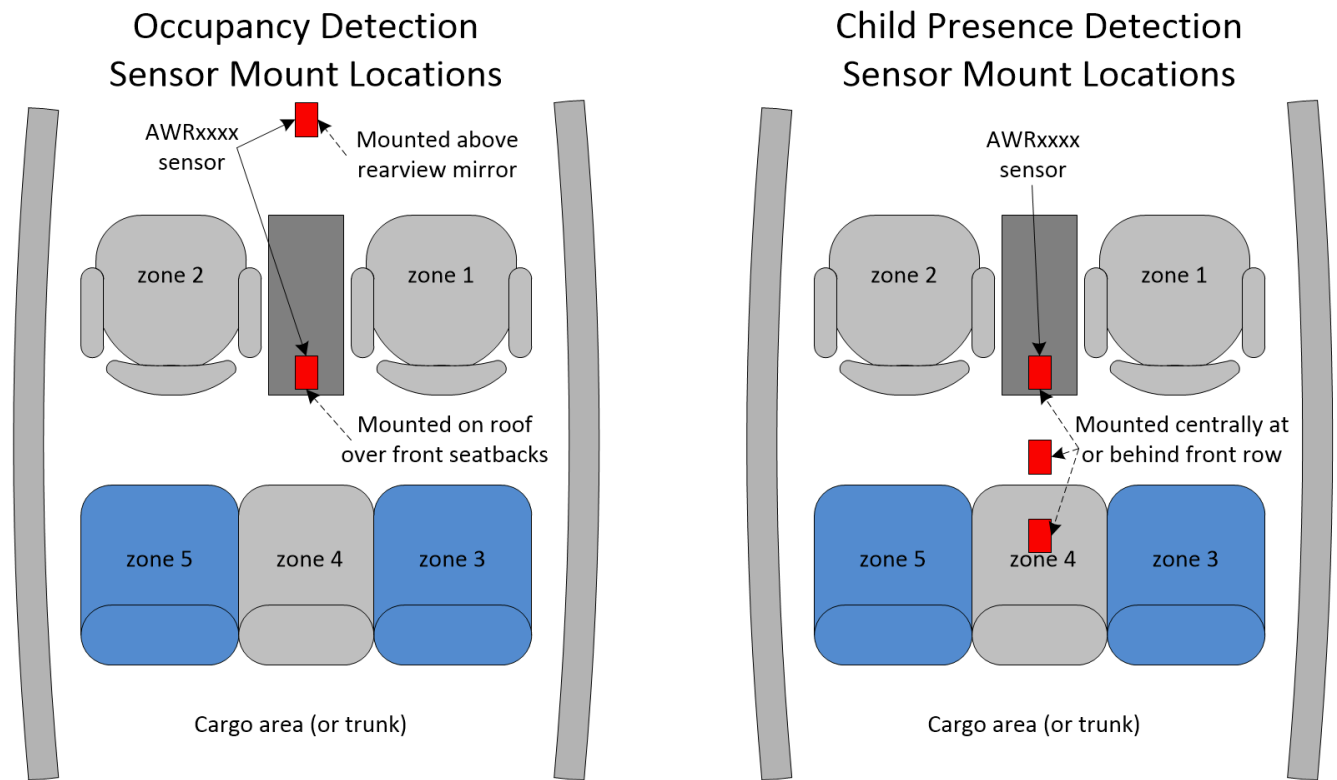
Item	Details
Mounting Hardware	The EVM needs to be mounted at a height of ~1.5-2.5m with a downtilt. An <b>adjustable clamp style smartphone adapter mount for tripods</b> and a <b>60-75" tripod</b> can be used to clamp and elevate the EVM. This is only an example solution for mounting; other methods can be used so far as setup specifications are met. For car testing, the EVM needs to be mounted on the car's interior roof. More below.
Computer	PC with Windows 7 or 10. If a laptop is used, please use the 'High Performance' power plan in Windows. 2.4Ghz processor minimum, 8GB RAM recommended.
Micro USB Cable	Due to mounting positions in the vehicle, an 8-20ft cable or USB extension cable is recommended.
Power Supply	5V, 3A with 2.1-mm barrel jack (center positive). The power supply can be wall adapter style or a battery pack with a USB to barrel jack cable.
Tape Measure	

## Software

Tool	Version	Required For	Details
mmWave Automotive Toolbox	2.9.x+	ESx.0 silicon	Contains all files (quickstart, visualizer and firmware source files) related to mmWave Occupancy Detection Lab
MATLAB Runtime	2017a (9.2)	GUI Visualizer	To run the quickstart visualizer the <b>runtime</b> is sufficient.
TI mmWave SDK	3.4.0.2+	Firmware Source Code	The latest <b>TI mmWave SDK</b> and all the related tools are required to be installed as specified in the mmWave SDK release notes
TI Emulators package	6.0.0576.0 or later	-	Upgrade to the latest using CCS update process (see SDK user guide for more details)
VOD Design Document	n/a	More Details /Info	Find it here: <a href="http://www.ti.com/lit/ug/tidue95/tidue95.pdf">http://www.ti.com/lit/ug/tidue95/tidue95.pdf</a>

## 2. Physical Setup

For best results, the EVM should be positioned as shown here for Occupancy Detection or Child Presence Detection (CPD), along with a chirp configuration matching the desired use case. For the front mount case, down tilt of the sensor is about 10 degrees. For the central roof mount case, you want to avoid having the antenna parallel with the floor, which will cause unnecessary reflections. A 10-15 angle towards the rear of the vehicle is preferred.



#### Benefits of mounting location:

##### Front (rearview mirror) Mount:

###### Pro:

- Excellent coverage of front row.
- Excellent coverage of vehicle exterior (intruder detection).

###### Con:

- Spacing of second row seats are somewhat compressed towards the center (this is antenna dependent) making seat separation a little more difficult.
- Second row footwell view is blocked by front row seats.

##### Central Roof Mount:

###### Pro:

- Addresses all CPD use cases.
- Excellent coverage of second row footwell (depending on mounting angle).
- Excellent coverage of second row.
- Can see most movement in cargo area (behind second row), depends on seat construction and/or line of sight.
- Typically can choose between:
  - front row, footwell and second row, or
  - footwell, second row and cargo area.

###### Con:

- Range/angle to each seat and footwell varies more than in front mount due to the almost parallel mounting angle.

The following configurations are provided to assist with VOD and CPD use cases. Please use the files with matching device names.

Chirp Configuration	Usage Case	Display Zones	Display	Description
od_demo_16xx_4zone.cfg	VOD	4	Heatmap	4 primary + 2 secondary zones.
od_demo_16xx_8zone.cfg	VOD	5	VOD, Heatmap	6 primary + 2 secondary zones.
od_demo_18xx_4zone.cfg	VOD	4	Heatmap	4 primary + 2 secondary zones.

Chirp Configuration	Usage Case	Display Zones	Display	Description
od_demo_18xx_8zone.cfg	VOD	5	VOD, Heatmap	6 primary + 2 secondary zones.
od_demo_18xx_cpd.cfg	CPD	1	CPD, Heatmap	2 primary + no secondary zones.
od_demo_68xx_4zone.cfg	VOD	4	Heatmap	4 primary + 2 secondary zones.
od_demo_68xx_8zone.cfg	VOD	5	VOD, Heatmap	6 primary + 2 secondary zones.
od_demo_68xx_cpd.cfg	CPD	1	CPD, Heatmap	2 primary + no secondary zones.

It is **STRONGLY** recommended that you follow the procedures at the end of this document for adjusting zone positions, collecting data and running the training tools to generate new coefficients. This should be done before any serious testing is performed. Also, there is a new training guide in docs/VOD\_coeff\_training\_steps.pdf that gives step by step instructions.

### 3. Flash the Device

- Power on the EVM using a 5V/3A power supply.
- Flash the following image using Uniflash

Image	Location
Meta Image 1/RadarSS	C:<install_dir>\front_mount_occupancy\prebuilt_binaries\oddemo_xxxx.bin

Expand for help using Uniflash



### 4. Choose Visualizer Setup Settings

Before running the demo either in Matlab or from DOS, you will need to know the COM port numbers for the EVM's User and Data UART ports. This is discussed in the pulldown section above titled "Expand for help using Uniflash". Once found, the COM port numbers will usually not change from run to run or boot to boot. These are the command line arguments for the Occupancy Detection demo gui:

Argument	Example/Purpose
Program Name	od_demo (it will either be a .exe (for DOS) or .m (for Matlab))
COM port (Data)	6
COM port (User)	5
Chirp Configuration	C:<install_dir>\front_mount_occupancy\chirp_configs\od_demo_1843_4zone.cfg
Operational Display Type	0 (0 = Zone Occupancy (VOD), 1 = Child Presence Detection (CPD), 2 = Heatmap)
	Note 1: Zone Occupancy must be run with an 8 zone config, with a front mounted sensor.
	Note 2: Child Presence Detection must be run with a CPD config, with an overhead mounted sensor.
Heatmap Display Type	1 (1 = Polar, 0 = Rectangular)
Flip Display in Azimuth	0 (0 = no flip, 1 = flip)

### 5. Run the Lab Visualizer (DOS prompt)

The following steps assume the AWR6843 EVM is flashed with the Occupancy Detection firmware.

- Mount the EVM as described above in the Test Setups.
- Attach the micro USB cable from the EVM to the host PC.

- Attach the 5V power adapter cable to the EVM.
- Open a DOS Command Window, and cd to `C:<install_dir>\front_mount_occupancy\gui`.
- At the DOS prompt, enter a command like one of these (refer to the above arguments):
  - [VOD, cartoon] `od_demo.exe 6 5 `C:\front_mount_occupancy\chirp_configs\od_demo_18xx_8zone.cfg 0 0 0`
  - [CPD, cartoon] `od_demo.exe 6 5 `C:\front_mount_occupancy\chirp_configs\od_demo_18xx_cpd.cfg 1 0 1`
  - [any, heatmap] `od_demo.exe 6 5 `C:\front_mount_occupancy\chirp_configs\od_demo_18xx_4zone.cfg 2 1 0`

After a successful start, the visualizer will begin to display occupancy at a frame rate, as shown in the next section. Again, what is displayed depends on the "demo mode" parameter of `oddemoParms` (found in the chirp configuration file), and the Operational Display Type on the command line, when the "demo mode" is "Operational".

To terminate the demo, perform the following steps:

- Click inside the GUI display to get focus.
- Press lowercase q.
- Click the "Exit" icon (X) in the top right of the Visualization window.

## 6. Understanding the Output

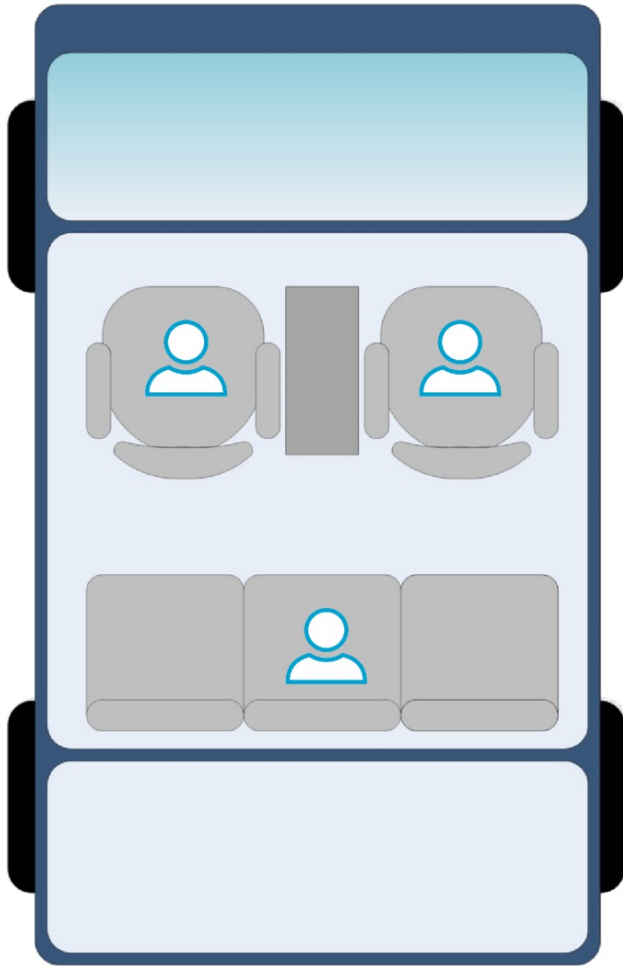
There are three operational displays, one of which will be displayed when the `oddemoParms` "mode" field is 1 (one). The display type is selected in the command line argument "Operational Display Type" described above (see Visualizer Setup Settings).

NOTE: Operational mode is selected via the first parameter of `oddemoParms`:

```
oddemoParms 1 8 0.001 0.50 18
```

### Zone Occupancy (VOD) Display

This display is selected when the command line argument "Operational Display Type" described above is set to zero. It will display five individual primary zones (2 front, 3 back) in a cartoon image of a vehicle. It requires use of an eight zone configuration (see the `chirp_configs` folder) and a front mounted sensor for proper use. Two narrow zones are overlapped to form the back center zone, and two zones are used as secondary zones for front to back row discrimination. If you modify the 8 zone configuration, please run it first with the heatmap display first to verify hotspot positioning, and then switch to this display once it is working.

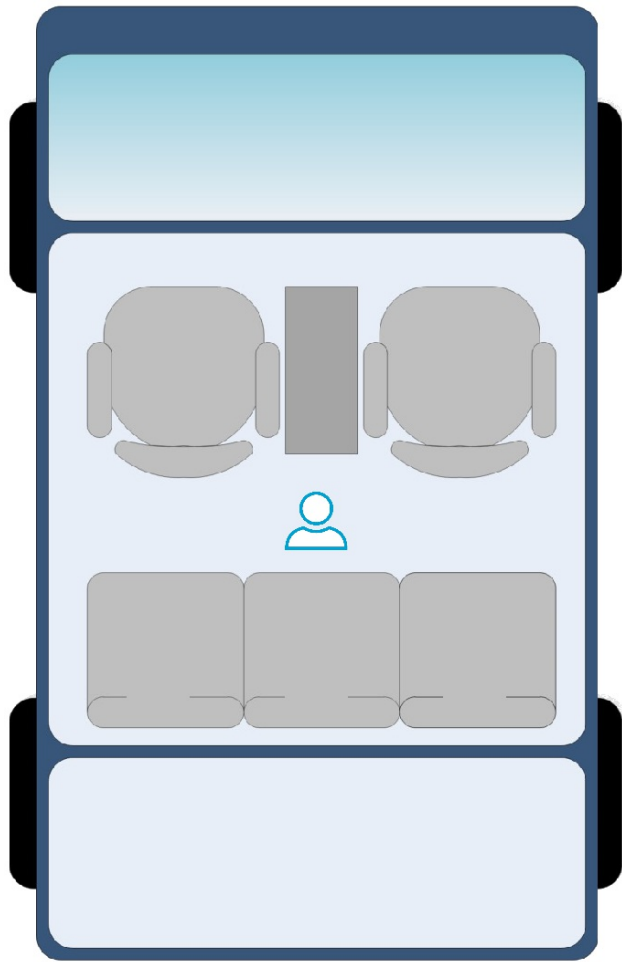


## Child Presence (CPD) Display

This display is selected when the command line argument "Operational Display Type" described above is set to 1 (one). It requires use of a two zone configuration (see the `chirp_configs` folder) and an overhead mounted sensor for proper use. This CPD display takes advantage of the new zone power localization\* that allows the occupant position to be output. Of the two zones that are defined, the first zone encompasses the entire back row plus footwell area, and a second non-used zone is set behind it. When a detection is indicated in the back row area, the position is used to place a cartoon image of a child in the nearest of six pre-defined positions.

\*The new "max 5x5" zone power determination searches each zone for the highest power 5x5 in the zone. The average power of the 5x5 is used for feature detection and the center of the 5x5 is output as the occupant's position.

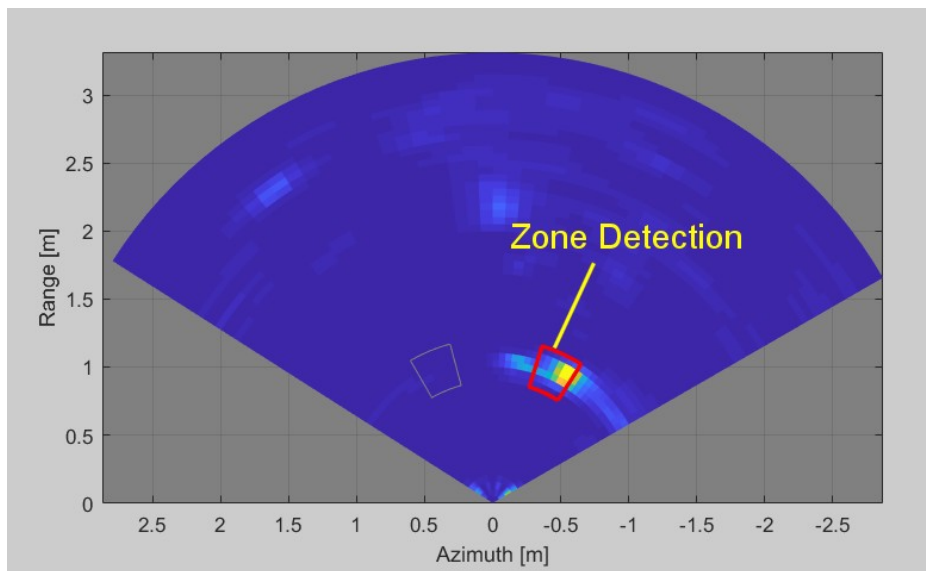
Note: This display will need tweaking in nearly every installation due to differences in interior geometries and sensor mounting position and angle. This will likely include changes to the zone position and size as well as the Matlab display function `displayCarCPD()`.



## Heatmap Display

This display is selected when the command line argument "Operational Display Type" described above is set to 2. The heatmap display is automatically scaled to the range of values within the heatmap for each frame. Blues are smaller values and Yellows are large. A bright spot indicates a higher energy return that has not been removed by the clutter removal algorithm. At times when there is no person in the zone a "bright spot" can actually be relatively small values because of the automatic scaling. When a person enters the scene, the scaling will adjust and the person will be shown as a bright spot with everything else fading to smaller value colors.

With the heatmap display, a zone boundary will turn red when the zone is occupied, and gray when not occupied. This display will use secondary zones if defined, which means if the primary zone is above threshold but the secondary zone is not, the zone boundary will not turn red.



Two widgets are provided in the heatmap display to aid in using the output:

- The Record checkbox starts recording the heatmaps to a file, up to 192 frames. You must uncheck the checkbox for the file to be saved. The file(s) will be saved where the gui is run, and will be named log\_XXX.mat, starting with log\_001.dat, incrementing in number.
- The Count checkbox starts a running frame counter, and with it, the count of positive detections in each zone. Unchecking the checkbox stops the counters. Checking it again will restart them from zero.

**IMPORTANT NOTE:** The Record checkbox is now only enabled in Data Collection Mode! The demo's mode is selectable via the oddemoParms command described below.

**NOTE on Primary and Secondary zones:** By default, a zone is a primary zone. A primary zone is displayed in the GUI displays. A secondary zone is used to aid in the decision making for a primary zone and is not displayed in the operational displays. A zone is identified as a secondary zone with the **secZoneDef** command described below. These commands are not sent to the device, and are only used in the GUI. When a secondary zone is associated with a primary zone via the **secZoneDef** command, the primary zone decision will not be positive unless both primary and secondary zones are above the averaging threshold.

## Developer's Guide

### Building the Firmware from Source Code

#### 1. Prerequisites for Firmware

The [software prerequisites](#) must be met before continuing!

To verify proper installations, navigate to **C:\ti** and ensure that the following tools have been installed in the *EXACT* directory specified.

Tool	Version	Folder Path	Download link & Details
CCS	8.0 or later	C:\ti\ccsv8	<b>Download link</b> Note: CCSv6.x cannot be used
TI SYS/BIOS	6.73.1.01	C:\ti\bios_6_73_01_01	Included in mmwave sdk installer
TI ARM compiler	16.9.6.LTS	C:\ti\ti-cgt-arm_16.9.6.LTS	Included in mmwave sdk installer
TI DSP compiler	8.3.3	C:\ti\ti-cgt-c6000_8.3.3	Version 8.1.3 must be downloaded and installed. <b>Download link</b>
XDC	3.50.8.24	C:\ti\xdctools_3_50_08_24_core	Included in mmwave sdk installer
C64x+ DSPLIB	3.4.0.0	C:\ti\dsplib_c64Px_3_4_0_0	Included in mmwave sdk installer
C674x DSPLIB	3.4.0.0	C:\ti\dsplib_c674x_3_4_0_0	Included in mmwave sdk installer
C674x MATHLIB	3.1.2.1	C:\ti\mathlib_c674x_3_1_2_1	Included in mmwave sdk installer
mmwave device support packages	1.5.3 or later	-	Upgrade to the latest using CCS update process (see SDK user guide for more details)
TI Emulators package	6.0.0576.0 or later	-	Upgrade to the latest using CCS update process (see SDK user guide for more details)

#### 2. Import Lab Project



The demo source now provides MSS and DSS projectspec files for each of these devices: AWR1642BOOST, AWR1843BOOST and IWR6843ISK. The resulting CCS project names will be as follows:

CCS Projects spec	Imported CCS Project Name
oddemo_16xx_dss.projects spec	oddemo_16xx_dss
oddemo_16xx_mss.projects spec	oddemo_16xx_mss
oddemo_18xx_dss.projects spec	oddemo_18xx_dss
oddemo_18xx_mss.projects spec	oddemo_18xx_mss
oddemo_68xx_dss.projects spec	oddemo_68xx_dss
oddemo_68xx_mss.projects spec	oddemo_68xx_mss

You only need to import the MSS and DSS projects for your device. The DSS is for the C674x DSP core and the MSS project for the R4F core. These need to be imported to CCS and compiled to generate firmware for the mmWave sensor.

- Start CCS and set the workspace as desired.
- Import the MSS and DSS projects below to CCS using either TI Resource Explorer in CCS or CCS Import Projects specs method:
  - (choose the versions matching your device, eg, 16xx, 18xx or 68xx)
  - **oddemo\_68xx\_dss**
  - **oddemo\_68xx\_mss**

Expand for details on importing via TI Resource Explorer in CCS

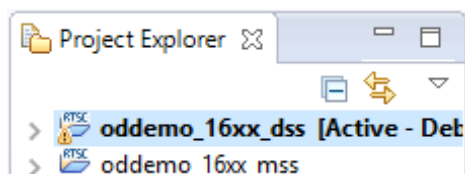


Expand for details on importing via CCS Import Projects specs



### Successful Import to IDE

After using either method, both project should be visible in **CCS Project Explorer** (Note, the actual project names will depend on the projects imported. 16xx projects are shown here)



### Project Workspace

When importing projects to a workspace, a copy is created in the workspace. All modifications will only be implemented for the workspace copy. The original project downloaded in mmWave Automotive Toolbox is not touched.

## 3. Build the Lab

### Build DSS Project

The DSS project must be built before the MSS project, because the MSS project will add the DSS' .bin file into the binary that will be flashed to the device.

The DSS project must be built using compiler version 8.3.3. To check the build settings, select **oddemo\_18xx\_dss** and right click on the project to select **Show build settings....** Under the **General** tab, the **Advanced Settings** section has a drop down menu for **Compiler Version**. Ensure that it reads **TI v8.3.3**.

With the `odddemo_18xx_dss` project selected in **Project Explorer**, right click on the project and select **Rebuild Project**. Selecting **Rebuild** instead of **Build** ensures that the project is always re-compiled. This is especially important in case the previous build failed with errors.



### Successful DSS Project Build

In the **Project Explorer** panel, navigate to and expand `odddemo_18xx_dss > Debug` directory. The project has been successfully built if the following files appear in the **Debug** folder:

- `odddemo_18xx_dss.bin`
- `odddemo_18xx_dss.xe674`

## Build MSS Project

After the DSS project is successfully built, select `odddemo_18xx_mss` in **Project Explorer**, right click on the project and select **Rebuild Project**.



### Successful MSS Project Build

In the **Project Explorer** panel, navigate to and expand `odddemo_18xx_mss > Debug` directory. The project has been successfully built if the following files appear in the **Debug** folder:

- `odddemo_18xx_mss.bin`
- `odddemo_18xx_mss.xer4f`
- `odddemo_18xx.bin`



### Build Fails with Errors

If the build fails with errors, please ensure that all the [prerequisites](#) are installed as mentioned in the mmWave SDK release notes.

## 4. Execute the Lab

There are two ways to execute the compiled code on the EVM:

- Deployment mode: the EVM boots autonomously from flash and starts running the bin image
  - Using Uniflash, flash the `odddemo_18xx.bin` found at  
`<PROJECT_WORKSPACE_DIR>\odddemo_18xx_mss\Debug\odddemo_18xx.bin`
  - The same procedure for flashing can be use as detailed in the Quickstart [Flash the Device](#) section.
- Debug mode: enables connection with CCS while lab is running; useful during development and debugging

Expand for help with Debug mode:



After starting the lab on the AWR1843 using either method, the program will wait until a chirp configuration is sent to it via the "User" COM port.

## Visualizer Source Files

Working with and running the Visualizer source files requires a MATLAB License not just the MATLAB Runtime Engine

The detection processing chain are implemented both in the firmware and in Matlab, and can be selected independently by configurations in the chirp config and the gui arguments. The visualizer serves to read the UART stream from the device and plots the heatmap along with zone decisions.

Source files are located at `C:<install_dir>\front_mount_occupancy\gui`.

- **od\_demo.m**: the Matlab gui program which reads and parses the UART data for visualization.
- **od\_demo.exe**: the DOS executable version of the gui program.

Chirp Configuration Files are located at **C:<install\_dir>\front\_mount\_occupancy\chirp\_configs** . In addition to the normal mmWave chirp configuration CLI commands, there are several commands that are specific to the Occupancy Detection Demo:

Command	Parameters
guiMonitor	(this command has unique arguments for this demo)
	1 = send <b>Feature Vector</b> as a TLV to the UART (TLV is defined below)
	1 = send <b>Decision Vector</b> as a TLV to the UART. Note: Turning this off stops the display of zone boundaries.
	16, 32 = send the <b>Heatmap</b> as 16-bit integer or 32-bit float respectively. 0 = don't send. The GUI automatically adjusts to each format.
	NOTE: Heatmap size MUST be 32 for Data Collection Mode, and is best 16 for Operational and Zone Tuning modes.
zoneDef	2, 4 or 6 = number of zones, followed by the following four values for each zone. Note that you are defining 1, 2 or 3 pairs of zones.
	range start, specified as the row index into the heatmap
	range length, specified as the number of rows in the heatmap
	azimuth start, specified as the column index in the heatmap
	azimuth length, specified as the number of columns in the heatmap
	NOTE: secondary zones must be listed last, following primary zones
secZoneDef	(defines a zone as being secondary (a zone is primary by default))
	1-based secondary zone number
	number of primary zone numbers to follow
	list of primary zone numbers affected by this secondary zone
coeffMatrixRow	zone pair number (0 through 2)
	matrix row number (0 through 3)
	coefficients for the row (currently 6 values)
meanVector	zone pair number (0 through 2)
	5 values (mean vector used to calculate the feature extract vector)
stdVector	zone pair number (0 through 2)
	5 values (standard deviation vector used to calculate the feature extract vector)
rowNoise*	Generated row noise-floor values for a set of contiguous rows
	first row number (zero based)
	number of rows (number of values to follow)
	noise-floor values
oddemoParms	demo mode: 1=Operational, 2=Zone Tuning, 3=Data Collection

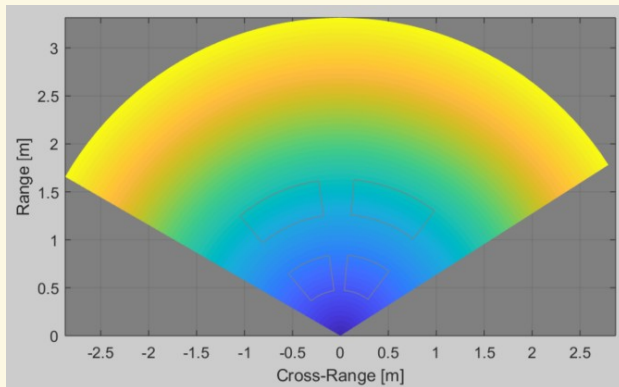
Command	Parameters
	window length (windowLen = number of frames). This window is used by the target to generate frame rate feature vector and decisions. Must be a multiple of 4.
	gamma value: diagonally-loading parameter in MVDR. When the covariance estimate is singular or near-singular, adding a small value along the diagonal avoids numeric stability issues (see VOD Design Doc referenced above).
	threshold value: A percent given as a decimal (eg. 0.50 = 50%). This is the threshold of positive frame rate detections to declare occupied. See the next parameter: "frame rate detection window".
	frame rate detection window: The number of frame detections averaged together to produce the "percent" value in the Detection TLV. This can be any size. Smaller numbers give faster response, larger numbers give more accurate results.
	heatmap smoothing: Smoothing factor to be applied to each cell of the heatmap compared to the previous frame's heatmap. If the current cell is less than prev_cell = previous cell times a factor, it is set to prev_cell. Eg, if factor = 0.75, then each cell in the current heatmap is set to the previous frame's cell x 0.75 only if less than that. Creates a smooth power fade. 0.0 disables the feature.

#### Important Notes on Arc Removal and rowNoise\* generation:

A side effect of MVDR is that an "arc" can be generated with some strong moving targets. This arc is extra energy in all azimuth cells along the affected range row of the heatmap. To combat this, the target code now sports an Arc Removal algorithm. This algorithm depends on knowing what the normal noise-floor value is for each row. The noise-floor is the average energy in the row when no moving targets are present.

The code will automatically generate these noise-floor values for your environment. This is how it works:

1) If rowNoise commands are not read from the config file, the code assumes that they need to be generated. In this case, the GUI will display this static screen for about 10 seconds:



Also, the command window will display the following message:

```
Done
oddemoParms 1 8 0.03 0.50 18
Done
sensorStart
Calculating empty FOV row noise-floor values...
```

When you see these, the code is calculating noise-floor values and will dump the commands to the command window that you can copy paste into your chirp config file, before the sensorStart command.

**IT IS CRITICAL** that during this time there are **NO** moving objects, people, etc. in the field of view or even nearby.

2) If rowNoise commands are read from the config file, the code will load these values and start normally.

#### Other notes:

1) Extremely bright (large RCS) targets can cause the 1D FFT to overflow, resulting in an arc that cannot be removed. Targets with this level of RCS will not be found inside a vehicle (an example would be a large corner reflector at close range). These arcs appear as a solid yellow line across the heatmap row.

2) noise-floor values will vary slightly from environment to environment, and so should be re-generated as needed. To do this, simply comment out any existing rowNoise commands and restart the demo.

3) If you change Tx Backoff or RxGain values in your profileConfig command, you will need to let the demo regenerate new noise-floor values for you.

## Data Packet Format

A TLV(type-length-value) encoding scheme is used with little endian byte order. For every frame, a packet is sent consisting of a fixed sized **Frame Header** and then a variable number of TLVs depending on what was selected via the guiMonitor command. There are 3 possible TLV types for the Occupancy Detection demo:

TLV Name	Type	Data Size (bytes)
Azimuth Range Heatmap	8	48 x 64 x 2 or 4 (size of short int or float)
Feature Vector	9	5 x 4 (size of float)
Decision Vector	10	4



## Frame Header

Size: 32 bytes

```
frameHeaderStructType = struct(...
    'sync',          {'uint16', 8}, ... % syncPattern in hex is: '02 01 04 03 06 05 08 07'
    'totalPacketLen', {'uint32', 4}, ... % In bytes, including header and 32 byte padding
    'platform',       {'uint32', 4}, ... % 0xA1642 or 0xA1843
    'frameNumber',    {'uint32', 4}, ... % Starting from 1
    'timeCpuCycles',  {'uint32', 4}, ... % Time in DSP cycles when the message was created
    'numDetectedObj', {'uint32', 4}, ... % not used in VOD
    'numTLVs',        {'uint32', 4}, ... % Number of TLVs in this message
```

Frame header in MATLAB syntax

## TLVs

The TLVs can be of type **RANGE\_AZIMUT\_HEAT\_MAP**, **FEATURE\_VECTOR**, or **DECISION**. Each TLV consists of a TLV header plus a unique data type.

### TLV Header

Size: 8 bytes

```
% TLV Type: 08 = Heatmap, 09 = Feature Vector, 10 = Decision Vector
tlvHeaderStruct = struct(...
    'type',          {'uint32', 4}, ... % TLV object identifier
    'length',        {'uint32', 4}); % TLV object length, in bytes
```

TLV header in MATLAB syntax

Following the header, is the TLV-type specific payload

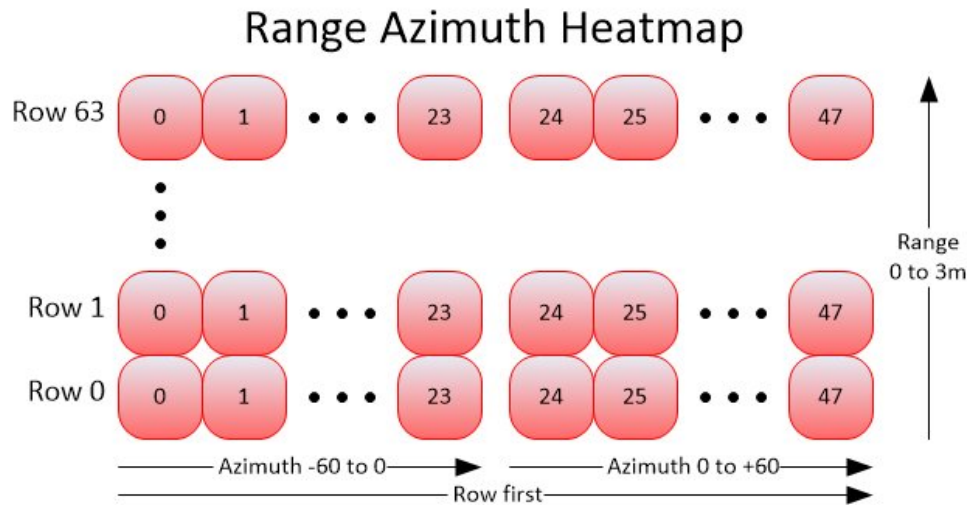
### Range Azimuth Heatmap TLV

Type: **RANGE\_AZIMUT\_HEAT\_MAP**

Size: 64 x 48 x sizeof (float or short int, depending on guiMonitor parameter)

The Occupancy Detection Range Azimuth Heatmap is a 2D array of floats or short ints, currently defined as 64 range rows with 48 azimuth angles per row. The total range is defined at 3 meters, so the range resolution of each

row is  $3\text{m} / 64 = 4.69\text{mm}$ . In terms of azimuth, zero degrees is perpendicular to the antennas, with 60 degrees of view on either side. Negative angles are to the left, with positive angles to the right. With 48 total angles, there are 24 angles per 60 degrees on each side, or 2.55 degrees per angle. The zone definition command (`zoneDef`) is specified as indexes into the heatmap.



## Feature Vector TLV

Type: FEATURE\_VECTOR Size: 5 x sizeof (float)

All values in the Feature Vector are normalized by the Mean Vector and Standard Deviation Vectors that are contained in the chirp configuration (.cfg) file.

```
featureVector = struct(...
    'avgPower1',    {'float', 4}, ... % Normalized zone 1 Power averaged over windowLen frames
    'avgPower2',    {'float', 4}, ... % Normalized zone 2 Power averaged over windowLen frames
    'powerRatio1',  {'float', 4}, ... % Normalized zone 1 Power ratio of current power averages
    'powerRatio2',  {'float', 4}, ... % Normalized zone 2 Power ratio of current power averages
    'crossCorr',    {'float', 4}, ... % Normalized Cross correlation value
```

Feature Vector Structure in MATLAB syntax

## Decision Vector TLV

Type: DECISION Size: 12 bytes per zone

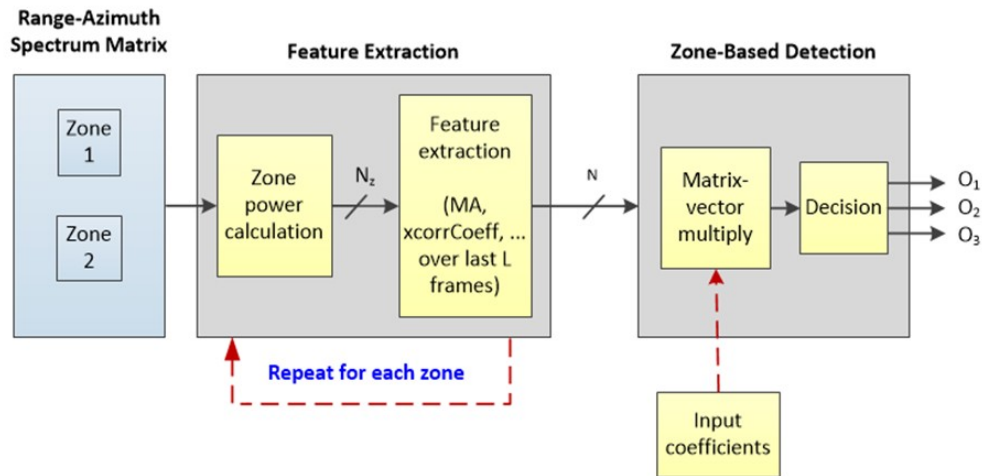
The Decision Vector is a mix of floats and 16-bit ints; four values per zone:

```
decisionVector = struct(...
    'percent',      {'float', 4}, ... % percentage of positive detections during the frame window period
    'power',        {'float', 4}, ... % windowed average zone power
    'rangeIdx',     {'uint16', 2}, ... % heatmap range idx for the center of the max 5x5
    'azimuthIdx',   {'uint16', 2}, ... % heatmap azimuth idx for the center of the max 5x5
```

Decision Vector Structure in MATLAB syntax

## Zone and Coefficient Training

Zone coefficients are used in the last stage of processing, to take the averaged zone power features and make an occupied/not-occupied decision for each zone. The coefficients in effect "teach" the code what the zones look like when occupied vs. empty.



To maximize the performance of these algorithms, the coefficients need to be tuned for each environment, or scene, in which the demo is used. We provide a tool and the following instructions to tune the demo parameters. The demo commands that are created by the training process are: (see the section above titled "Visualizer Source Files" for command parameters).

- zoneDef (this is adjusted manually as described below)
- coeffMatrixRow
- meanVector
- stdVector

Please note! A new resource has been added to the docs/ folder of this lab: VOD\_coeff\_training\_steps.pdf. This is a step-by-step guide through the process, using the new GUI that the demo provides for training (Data Collection Mode).

NOTE: Zone Tuning mode is selected via the first parameter of oddemoParms:

```
oddemoParms 2 8 0.001 0.50 18
```

Expand for details on tuning zone definitions



NOTE: Data Collection mode is selected via the first parameter of oddemoParms:

```
oddemoParms 3 8 0.001 0.50 18
```

Expand for details on training coefficients



## Need More Help?

- Find more details about VOD by referring to the [VOD Design document](#)
- Find answers to common questions on [mmWave E2E FAQ](#)
- Search for your issue or post a new question on the [mmWave E2E forum](#)

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