

Portable Ultrasound System for Blood Velocity Estimation

Project Report

Master Thesis

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Jeppe Hinrichs - s163555

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Contents

Contents	I
List of Figures	III
List of Tables	IV
Abbreviations	V
Glossary	VI
Nomenclature	VII
Reading comprehension	X
1 Introduction	1
1.1 Project scope	1
2 Theory	5
2.1 Ultrasound	5
2.1.1 Scattering	6
2.1.2 Attenuation	7
2.1.3 Transducer	8
2.1.4 Doppler effect	8
2.2 Flow Physics	10
2.2.1 Blood flow	12
2.3 Devices	12
2.3.1 Continuous-wave Flowmeter	13
2.3.2 Pulsed-wave Flowmeter	15
2.4 Blood Velocity Estimation	17
2.4.1 Spectral estimation	17
3 Synthesis	19
3.1 Control System	19
3.1.1 PlatformIO	19
3.1.2 Zephyr	20
3.2 Pulse-Width-Modulation Generator	20
3.3 Power Stage	21
3.4 Transmit/Receive Switch	21
3.5 Transducer	22
3.5.1 Impedance matching input	22
3.6 Preamplifier	22
3.7 Demodulation	23
3.8 Sample/Hold	23
3.9 Pulse-Repetition and Wall Filter	23
3.10 Amplifier	23
3.11 Mixer	23
3.12 Adder	23

4	Production	25
4.1	Graphs and charts	25
4.2	Tables and figures	28
4.3	Equations	30
4.4	Listings (code)	31
5	Examples of figures, tables, equations and listings	33
5.1	Graphs and charts	33
5.2	Tables and figures	36
5.3	Equations	38
5.4	Listings (code)	39
	Bibliography	41
A	Bill of Materials	44
B	Instruments	47

List of Figures

2.1	Particle displacement for a propagating ultrasound wave	5
2.2	Single element ultrasound transducer construction	8
2.3	Transducer types for acquiring B-mode images	9
2.4	Doppler effect diagram	10
2.5	Circulatory system of the human body	11
2.6	Diagram of ultrasound wave transmitted and reaching blood vessel with incident angle θ	12
2.7	Block diagram of continuous-wave flowmeter	13
2.8	Doppler signals in time and frequency domain showing demodulation effects	14
2.9	Block diagram of pulsed-wave flowmeter	15
2.10	Sampling for a gate pulsed wave system with a single range	16
2.11	Arterial sonogram with time-frequency and Doppler shift	17
3.1	Simplified overview of the system	19
3.2	Circuit diagram of power stage	21
3.3	Circuit diagram of switch (per channel)	22
4.1	Stacked column chart	25
4.2	Stacked bar chart	26
4.3	Grouped column chart	26
4.4	Line graph	26
4.5	Line graph with magnifying glass	27
4.6	Area graph	27
4.7	Scatter plot	27
4.8	Boxplot	28
4.9	The nodes short, V, R and L are presented here, but there a lot more . . .	28
4.10	Just a normal figure	29
4.11	A figure with two subfigures	30
4.12	A figure with four subfigures	30
5.1	Stacked column chart	33
5.2	Stacked bar chart	34
5.3	Grouped column chart	34
5.4	Line graph	34
5.5	Line graph with magnifying glass	35
5.6	Area graph	35
5.7	Scatter plot	35
5.8	Boxplot	36
5.9	The nodes short, V, R and L are presented here, but there a lot more . . .	36
5.10	Just a normal figure	37
5.11	A figure with two subfigures	38
5.12	A figure with four subfigures	38

List of Tables

1.1	Comparison of medical imaging modalities	3
1.2	Project specification	3
2.1	Approximate density, sound speed, and acoustic impedance of human tissue types	6
2.2	Approximate attenuation values for human tissue	7
2.3	Measured frequency shifts with a Doppler 3 MHz transducer at various velocities at a 45° incident angle	15
4.1	This is a booktabs table	28
4.2	Wrongly formatted table	29
4.3	Correctly formatted table	29
5.1	This is a booktabs table	36
5.2	Wrongly formatted table	37
5.3	Correctly formatted table	37
A.1	BOM	44
B.1	List of instruments used for solder work	47
B.2	List of instruments used for testing	47

Abbreviations

Notation	Description
<i>ADC</i>	analogue-to-digital converter
<i>BP</i>	band-pass
<i>CMUT</i>	capacitive micromachined ultrasound transducer
<i>CPU</i>	central processing unit
<i>CT</i>	computed tomography
<i>CW</i>	continuous-wave
<i>DSP</i>	digital signal processor
<i>DTU</i>	Danmarks Tekniske Universitet (Technical University of Denmark)
<i>I/O</i>	input/output
<i>IC</i>	integrated circuit
<i>KAIST</i>	Korea Advanced Institute of Science and Technology
<i>low-res</i>	low resolution
<i>MCU</i>	microcontroller unit
<i>MRI</i>	magnetic resonance imaging
<i>PSD</i>	power spectral density
<i>PW</i>	pulsed-wave
<i>RTOS</i>	real-time operating system
<i>US</i>	ultrasound

Glossary

Notation	Description
adiabatic	Any process that happens without heat gain or loss is considered adiabatic
Doppler effect	A change in frequency of a wave in relation to an observer who is moving relative to the wave source
transcutaneous	Applied across the depth of the skin without invasive penetration

Nomenclature

Name	Unit	Description
Input filter		
V_{ref}	V	Reference voltage
C_{hp}	F	High pass filter capacitor
R_{hp}	Ω	High pass filter resistor
f_{hp}	Hz	High pass cut-off frequency
C_{lp}	F	Low pass filter capacitor
R_{lp}	Ω	Low pass filter resistor
f_{lp}	Hz	Low pass cut-off frequency
A_v	1	Amplification factor
Modulator		
R_1	Ω	AIM voltage divider resistor
R_2	Ω	AIM voltage divider resistor
R_{in}	Ω	AIM input resistor
R_{fb}	Ω	AIM feedback resistor
C_1	F	AIM capacitor
V_{in}	V	Input signal voltage
V_{span}	V	Voltage range of input signal
V_{pwm}	V	PWM signal
V_H	V	V_{pwm} high level voltage
V_L	V	V_{pwm} low level voltage
V_{out}	V	V_{pwm} voltage range ($V_H - V_L$)
V_{hys}	V	Hysteresis voltage
V_{hw}	V	Hysteresis width
$V_{\text{th}H}$	V	Hysteresis threshold upper voltage
$V_{\text{th}L}$	V	Hysteresis threshold lower voltage
V_c	V	PWM carrier voltage
V_{cH}	V	PWM carrier upper voltage
V_{cL}	V	PWM carrier lower voltage
f_{sw}	Hz	PWM signal frequency
D	1	PWM signal duty cycle
t_H	s	PWM carrier charge time

Continued on next page

Name	Unit	Description
t_L	s	PWM carrier discharge time
τ	1	PWM carrier charge constant
R_{th}	Ω	PWM carrier thevenin resistance
f_{idle}	Hz	PWM signal idle switching frequency
k_2	1	R_{fb} , R_{in} voltage divider
Gate driver		
D_{dt}	1	Dead-time circuit diode
R_{dt}	Ω	Dead-time circuit resistor
C_{dt}	F	Dead-time circuit capacitor
V_C	V	Dead-time circuit supply voltage
V_s	V	IC supply voltage
t_c	s	Charging circuit time
Power stage		
V_{DD}	V	Power supply voltage
Q_1, Q_2, Q_3, Q_4	1	Power stage switches
V_g	V	Gate driver signal
V_o	V	Output voltage
I_o	A	Output current
R_{BTL}	Ω	Speaker equivalent load resistance
Output filter		
R_f	Ω	Output filter single-ended load
C_{BTL}	F	Output filter differential capacitance
C_f	F	Output filter single-ended capacitance
L_f	H	Output filter inductance
ΔI_L	A	Output filter ripple current
Q	1	Output filter quality factor
f_c	Hz	Output filter cut-off frequency
ω_n	rads^{-1}	Output filter natural frequency
ζ	1	Output filter damping ratio

Continued on next page

Name	Unit	Description
Shunt regulator		
R_{sh}	Ω	Shunt current limiting resistor
I_K	A	Shunt cathode current
$I_{K_{\max}}$	A	Shunt maximum cathode current
$I_{K_{\min}}$	A	Shunt minimum cathode current
I_{su}	A	Shunt supply current
R_{A1}	Ω	Shunt adjust resistor 1
R_{A2}	Ω	Shunt adjust resistor 2
C_L	F	Shunt load capacitance
$V_{\text{ref}_{\text{IC}}}$	V	Shunt internal reference voltage

Reading comprehension

This section of the report will explain to the reader how to reference this document and explain the fundamental structure of the project as well as the report. Throughout the report, the reader will be assumed to be knowledgeable of basic circuit analysis and familiar with standard abbreviations typically used in electrical engineering. If not, readers can refer to the denotation section at the beginning of the report. It is assumed that the reader has a basic knowledge on the science of physics, electrical engineering, computing, and circuit analysis.

Please refer to Abbreviations, Glossary, and Nomenclature pages for explanations to terms found within the report.

Sources

Calculus expressions present in the report will typically have a reference explaining their origin. All references are prominently displayed with square brackets and a number, directing to the appendix in the last section of the report.

1 Introduction

The progress of diagnostic imaging has advanced significantly during the 20th century. As the cost of high-speed computational systems has grown increasingly accessible, so has the use of medical imaging become prominent. Potentially millions of people have been spared painful exploratory surgery through non-invasive diagnostic imaging. And thus, lives can be saved by early diagnosis and intervention through medical imaging. Advancements in scientific visualisation have in turn generated more complex datasets of increased size and quality. The four major technologies used are ultrasound (*US*), X-ray, computed tomography (*CT*), and magnetic resonance imaging (*MRI*). Each technology has distinct advantages and disadvantages in biomedical imaging, and thus each is still relevant for modern medicine. Table 1.1 contains a comparison and summary of the various fundamental diagnostic imaging modalities.

Since 2004, medical imaging has been reported to have been performed more than 5 billion times [8], and later numbers from 2011 show a general doubling and in particular, a tenfold increase in ultrasound examinations between 2000 and 2011 [20]. Recent data reveal that this trend of doubling has continued throughout the years 2010 to 2020 [32], and reveal that even though patient processes were disrupted during the global SARS-CoV-2 pandemic, the number of medical imaging examinations per 1000 patients still increased. The reasons for this and, particularly, why ultrasound has seen a significant increase in use, can be attributed to its high, but inconsistent, resolution, cost-effectiveness, portability, and real-time interventional imaging. The downside of ultrasound is its limited penetration and restrictions for use in certain body parts. When comparing soft tissue examinations, which ultrasound is limited to, both *CT* and *MRI* can image the entire body with consistent resolution and contrast, but are more expensive and have poor portability due to the immense size of their hardware.

The cardiovascular system, which transports oxygen and nutrients to tissue, produces a complex flow pattern that causes velocity fluctuations. Several cardiovascular diseases are also known to cause abnormal blood flow. As mentioned above, ultrasound is a powerful tool for performing non-invasive imaging of the cardiovascular system [16], [19], and has no adverse risk to patients. Determining power spectral density (*PSD*) of a received signal is a common way to estimate blood velocity. A processed image of *PSD* over time is commonly known as a sonogram, where changes in blood velocity over time can be seen.

1.1 Project scope

The aim of this project is to study the application of ultrasound in the context of blood flow measurements. Various scientific articles have been studied to gain knowledge of previous research [4]–[6], [9], [11], [13]–[15], [17], [18], [24], [25], [27]–[30]. In addition, textbooks [19]–[21] have also been instrumental in forming a solid knowledge base for the thesis. The desire is to build upon the vast knowledge already gathered by prominent researchers in the field of ultrasound systems for blood velocity estimation. Finally, using the knowledge gained, we designed and implemented an electronic device capable of performing these measurements using a novel approach. The system used in this project is called an Ultrasound Doppler flow-meter. Ultrasound Doppler flow-meters can be used to measure the velocity of blood flow in the human body. This is commonly done to assess the health of blood vessels and to diagnose and monitor conditions such as arteriosclerosis (hardening

of the arteries) and deep vein thrombosis (blood clots in the veins). To measure blood velocity with an ultrasound Doppler flow-meter, a handheld probe is placed on the skin over the area of interest, such as an artery or vein. The probe contains a transducer that emits high-frequency ultrasound waves and receives the reflected waves. The Doppler shift in the frequency of the reflected waves is caused by the movement of the blood cells, and it is proportional to the velocity of the blood flow. The probe is connected to a portable ultrasound machine, which processes the Doppler shift and displays the velocity of the blood flow on a screen. The machine can also produce a color-coded map of the blood flow, which allows the user to visualize the velocity of the blood at different points within the vessel. Ultrasound Doppler flow-meters are non-invasive and safe to use, and they provide a quick and easy way to measure blood velocity. However, they are not always accurate, especially in cases where there is a high degree of turbulence or when there are air bubbles or solid particles present in the blood. They are also limited in their ability to measure blood flow in small vessels or in deep tissues. The goals of the project are written in table 1.2.

The project is conducted under the guidance of advisors from the affiliated institutions Danmarks Tekniske Universitet (Technical University of Denmark) (*DTU*), Department of Electrical Engineering, Department of Applied Mathematics and Computer Science, and Korea Advanced Institute of Science and Technology (*KAIST*) at the Brain/Bio Medical Microsystems Laboratory. The report is divided into five chapters, and the first part is an introduction to the project. The second chapter will focus on explaining the theory of the topic of the project. The third chapter focuses on the synthesis of a system for experimental testing. The fourth chapter explains the production of the hardware. The fifth chapter will explain the testing methodology performed on the hardware. Finally, additional documentation of testing, code, circuit diagrams, and laboratory setups can be found in the appendix.

Table 1.1: Comparison of medical imaging modalities [20]

Modality	Ultrasound	X-ray	CT	MRI
Topic	Longitudinal, shear, mechanical properties	Mean X-ray tissue absorption	Local tissue X-ray absorbtion	Biochemistry ($T1$ and $T2$)
Access	Small windows adequate	2 sides needed	Circumferential around body	Circumferential around body
Spatial resolution	0.2 mm to 3 mm ^a	~ 1 mm	~ 1 mm	~ 1 mm
Penetration	3 cm to 25 cm ^b	Excellent	Excellent	Excellent
Safety	Excellent	Ionizing radiation	Ionizing radiation	Very good
Speed	Real-time	Minutes	20 minutes	Varies [†]
Cost	\$	\$	\$\$	\$\$\$
Portability	Excellent	Good	Poor	Poor
Volume coverage	Real-time 3D volumes, improving	2D	Large 3D volume	Large 3D volume
Contrast	Increasing (shear)	Limited	Limited	Slightly flexible
Intervention	Real-time 3D increasing	No ^c	No	Yes, limited
Functional	Functional ultrasound	No	No	fMRI

^a Frequency and axially dependent.^b Frequency dependent.^c Fluoroscopy limited.[†] Typical: 45 minutes, fastest: Real-time (*low-res*).

Table 1.2: Project specification

Project specification
Study and research ultrasound and its principles and applications
Design and implement a device for ultrasound blood velocity estimation
Investigate and test the device in an experimental setting
Validate results with commercial equipment
Make quantifiable performance measurements on system
Write a technical report documenting the project work

2 Theory

This chapter explains the overall theory that forms the fundamental principles of this project. Initially, the characteristics of ultrasound will be explained from an acoustics standpoint. Then, a brief overview of the systemic circulation is explained in vivo. Lastly, the various types of flow-meters are outlined with their strengths and weaknesses.

2.1 Ultrasound

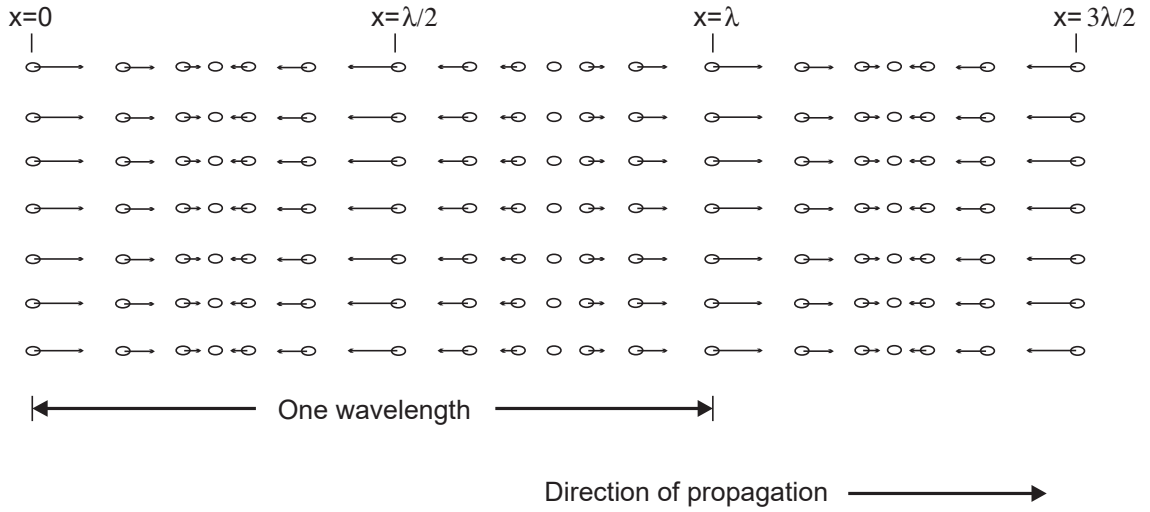


Figure 2.1: Particle displacement for a propagating ultrasound wave [19]

US is a technology that transmit sound wave with frequencies above the audible range (20 to 20 000 Hz) to mechanically vibrate matter. The particles in the medium would be at rest and distributed uniformly before any disturbance. The wave propagates as a disturbance and the particles oscillate around their mean position due to the presence of the ultrasonic wave. Typically the US frequency band used in clinical settings are from 1 to 15 MHz [20]. Figure 2.1 visualizes the propagation of a plane wave in matter. The oscillation occurs parallel to the wave's direction, making it longitudinal, and the disturbance will propagate with the variable c , which is determined by the medium and is given by eq. (2.1).

$$c = \sqrt{\frac{1}{\rho_0 \kappa_S}} \quad (2.1)$$

Where ρ_0 is the mean density (kgm^{-3}) and κ_S is the adiabatic compressibility (m^2N^{-1}). Since in the majority of cases, the propagation of ultrasound is linear, it is assumed in this work. The acoustic pressure of the harmonic plane wave is expressed by eq. (2.2).

$$p(t, z) = p_0 e^{j(\omega t - kz)} \quad (2.2)$$

And propagates along the z -axis. ω is the angular frequency, k is the wave number and is expressed by $k = \omega/c = 2\pi/\lambda$, and p_0 is the acoustic pressure amplitude. A spherical wave is expressed by eq. (2.3)

$$p(t, r) = p_0 e^{j(\omega t - kr)} \quad (2.3)$$

Where r is radial distance, and is defined in a polar coordinate system. For each time instance, the acoustic pressure $p(t, r)$ is constant over a fixed radial position. In this scenario, the pressure amplitude is given by $p_0(r) = k_p/r$, where k_p is a constant since the energy of the outgoing wave must be constant. Particle speed u is dependent on the pressure caused by a wave expressed by eq. (2.4)

$$u = \frac{p}{Z} \quad (2.4)$$

Where Z is the characteristic acoustic impedance, defined as the ratio of acoustic pressure to particle speed at a given position in the medium and is expressed by eq. (2.5).

$$Z = \rho_0 c \quad (2.5)$$

Characteristic acoustic impedance Z is one of the most significant variables in the characterization of propagating plane waves. Reference values for density, speed of sound, and characteristic acoustic impedance can be seen in table 2.1.

Table 2.1: Approximate density, sound speed, and acoustic impedance of human tissue types [19]

Medium	Density (ρ_0) kg/m ³	Speed of sound (c) m/s	Acoustic impedance (Z) kg/(m ² s)
Air	1.2	333	0.4×10^3
Blood	1.06×10^3	1566	1.66×10^6
Bone	$1.38\text{--}1.81 \times 10^3$	2070–5350	$3.75\text{--}7.38 \times 10^6$
Brain	1.03×10^3	1505–1612	$1.55\text{--}1.66 \times 10^6$
Fat	0.92×10^3	1446	1.33×10^6
Kidney	1.04×10^3	1567	1.62×10^6
Lung	0.4×10^3	650	0.26×10^6
Liver	1.06×10^3	1566	1.66×10^6
Muscle	1.07×10^3	1542–1626	$1.65\text{--}1.74 \times 10^6$
Spleen	1.06×10^3	1566	1.66×10^6
DI	1×10^3	1480	1.48×10^6

In the following sections, various acoustic wave phenomena will be briefly described.

2.1.1 Scattering

A wave propagating through a medium continues in the same direction until it encounters a new medium. When this occurs, a portion of the wave is transmitted into the new medium with a change in direction. Because the scattered wave is the result of several contributors, it is necessary to define it statistically. The amplitude distribution is Gaussian [19] and can thus be fully described by its mean and variance. The mean value is zero because the dispersed signal is caused by variances in the acoustic characteristics in the tissue. The correlation between multiple data is what allows ultrasound to determine blood velocities. Because minor movements have a significant correlation, it is feasible to discover alterations in location by comparing sequential measurements of moving structures, such as blood cells. In medical ultrasound, only one transducer is used to transmit and receive, and only the backscattered signal is analysed. The power of the scattered signal is defined by the

scattering cross-section, which in small cases means a uniform intensity I_i , and is expressed by eq. (2.6).

$$P_s = I_i \sigma_{sc} \quad (2.6)$$

Where σ_{sc} is the scattering cross-section in square meters. The backscattering cross section is material dependant and determines the intensity of the scattering. If the dispersed energy is evenly emitted in all directions, the scattered intensity is given by eq. (2.7).

$$I_s = \frac{P_s}{4\pi R^2} = \frac{\sigma_{sc}}{4\pi R^2} \cdot I_i \quad (2.7)$$

Where R is distance to the scattering region [19]. This results in a spherical wave. A transducer with radius r gives the power P_r , presuming the attenuation and focus is neglected, and is expressed by eq. (2.8).

$$P_r = I_s \pi r^2 = \sigma_{sc} \frac{r^2}{4R^2} \cdot I_i \quad (2.8)$$

The backscattering coefficient, which characterizes scattering from a volume of scatterers, is another measure of scattering strength. It is defined as the average received power per steradian volume of scatterers when flooded with plane waves of unit amplitude and the unit is 1/cmsr. Backscattering coefficients in the blood are significantly lower than the backscattering coefficients from various tissue types. This poses a challenge when estimating blood flow close to tissue vessel walls [3], [19].

2.1.2 Attenuation

The ultrasonic wave will be reduced as it propagates through the tissue due to absorption and scattering. The attenuation in tissue is frequency dependent, with greater attenuation with increasing frequency. Because of absorption and dispersion, the ultrasonic wave will be attenuated as it travels through the tissue. The relationship between attenuation, distance travelled, and frequency is often linear. Attenuation in the tissue occurs as a result of both dispersion, which spreads energy in all directions, and absorption, which turns it into thermal energy.

Table 2.2: Approximate attenuation values for human tissue [19]

Tissue	Attenuation dB/(MHz · cm)
Liver	0.6–0.9
Kidney	0.8–1
Spleen	0.5–1
Fat	1–2
Blood	0.17–0.24
Plasma	0.01
Bone	16–23

The pressure of a wave propagating in z -direction decreases exponentially expressed by eq. (2.9)

$$p(z) = p(z = 0)e^{-\alpha z} \quad (2.9)$$

Where $p(z = 0)$ is the pressure in the point of origin and α is the attenuation coefficient. The attenuation coefficient unit is Npcm^{-1} and, alternatively, dBcm^{-1} with the relationship described in eq. (2.10).

$$\alpha = \frac{1}{z} \ln \frac{p(z = 0)}{p(z)} \quad (2.10a)$$

$$\alpha(\text{dBcm}^{-1}) = 20(\log_{10} e)\alpha(\text{Npcm}^{-1}) = 8.68\alpha(\text{Npcm}^{-1}) \quad (2.10b)$$

The significance of absorption and scattering in ultrasonic attenuation in biological tissues is a point of contention. Scattering adds just a few per cent to attenuation in most soft tissues. As a result, it is fair to conclude that absorption is the primary mechanism of ultrasonic attenuation in biological tissues [21].

2.1.3 Transducer

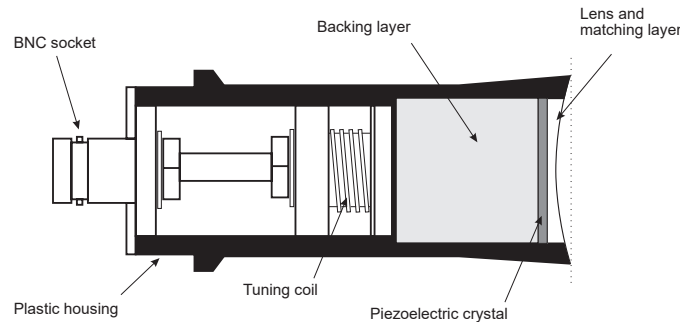


Figure 2.2: Single element ultrasound transducer construction [19]

A layperson knows transducers as speakers and microphones in the context of PA systems. In the case of medical *US* it is the device that generates the acoustic pressure field, which is emitted into the tissue. The transducer has a piezoelectric crystal inside the housing. When excited, this crystal emits ultrasound waves toward flowing blood. The red blood cells will reflect a fraction of the emitted waves. These reflected waves are of a different frequency than the transmitted wave. If the red blood cells move away from the transducer, the frequency will be lower. If the red blood cells are moving towards the transducer, the frequency will be higher. This is caused by the Doppler effect. The reflected ultrasonic waves return to the crystal and are converted back into electrical signals. The single-element transducer shown in fig. 2.2 has a minimal imaging window and has to be mechanically manipulated to obtain a wide window, which is unfeasible for responsive high-frequency imaging. Thus, usually, a transducer array is used. Various types of *US* transducer exist with different strengths and weaknesses, shown in fig. 2.3.

2.1.4 Doppler effect

The Doppler effect is a phenomenon in which an observer perceives a shift in the frequency of sound emitted from a source when either the source or the observer is moving, or both are moving. The reason for the perceived change in frequency is visualised in fig. 2.4. In diagram (a), the source S_p is stationary and produces a spherical distribution pattern of the wave with the perceived frequency of the observer is given by $f = c/\lambda$, where c is the velocity of the wave in the medium and λ is the wavelength. In diagram (b), the sound source is moving towards the right with a velocity v . The locomotion of the source changes the distribution pattern and causes a longer wavelength on the left, indicating a lower

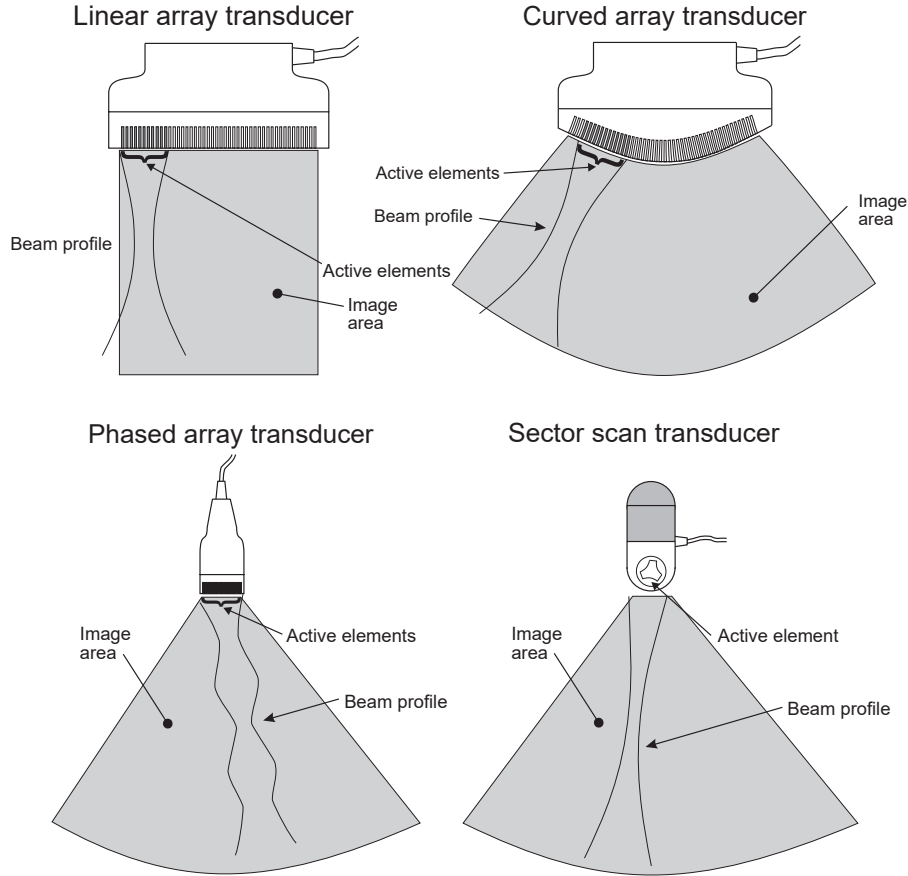


Figure 2.3: Transducer types for acquiring B-mode images [19]

perceived frequency, and a shorter wavelength on the right, indicating a higher perceived frequency, both denoted as λ' in the diagram. In the case of the observer on the right side, the perceived frequency becomes eq. (2.11).

$$f' = \frac{c}{\lambda} = \frac{c}{\lambda - vT} = \frac{c}{(c - v)T} = \frac{c}{c - v} \cdot f_0 \quad (2.11)$$

And viceversa, on the left side, the perceived frequency becomes eq. (2.12).

$$f' = \frac{c}{c + v} \cdot f_0 \quad (2.12)$$

Where

Hvad mangl

This perceived difference between the frequency that is transmitted from the source f_0 , and the perceived frequency f' is also called the Doppler frequency, f_d . When these connections are combined, the Doppler frequency for a source moving with velocity v and an observer travelling with velocity v' is given by eq. (2.13).

$$f_d = f' - f = \left(\frac{c + v'}{c - v} - 1 \right) \quad (2.13)$$

If both source and observer are moving with the same velocity, v , assuming $c \gg v$, the v cancels out and the expression is reduced to eq. (2.14).

$$f_d = \frac{2vf}{c} \quad (2.14)$$

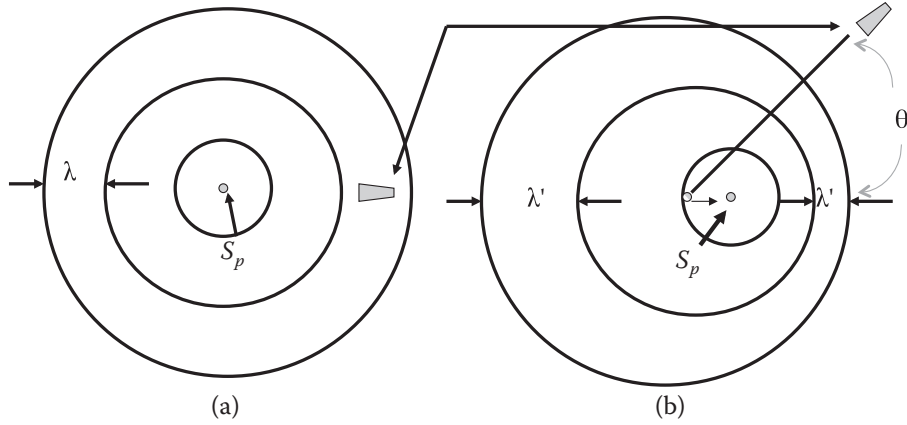


Figure 2.4: Doppler effect diagram. A stationary observer perceives a change in the frequency of a wave generated by a moving source toward the observer as a result of a wavelength shift from λ to λ' . In (a), the source is still. In (b), the source is moving at a velocity v . [21]

If the velocity of the moving source is traveling with an incident angle θ , the v in eq. (2.14) is replaced with $v(\cos \theta)$. This results in the expression found in eq. (2.15) and forms the basis for applied Doppler effect measurements.

$$f_d = \frac{2v(\cos \theta)f}{c} \quad (2.15)$$

The Doppler effect is used in ultrasonic Doppler devices used to image blood flow transcutaneously. An ultrasonic transducer in these devices sends ultrasonic waves into a blood artery, and the scattered radiation from moving red cells is measured by either the same transducer or a second transducer. The Doppler frequency, which is determined by the velocity of red blood cells, is extracted using modern electronic demodulation techniques.

2.2 Flow Physics

The flow physics of the human circulatory system are sophisticated, and numerous nonstationary flow patterns emerge. The human circulatory system takes care of transporting oxygen and nutrients to organs, as well as disposing of waste products produced by metabolism. It is possible because the blood within the circulatory system contains several smaller subcomponents, such as plasma and formed cellular elements that perform these vital functions. Initially, blood is discharged from the left ventricle of the heart through the aorta and travels to all areas of the body through multiple branches of the arterial tree. When blood flows through the arteries, it enters smaller channels known as arterioles. These arterioles lead to a network of tiny capillaries through which nutrients and waste materials are exchanged between the blood and the organs. The capillaries connect to form a network of venules, which supply the veins and deliver blood back to the heart. This system, in its entirety, is called systemic circulation. A diagram of the circulatory system as described above can be seen in fig. 2.5. In summary, when examining the elements that comprise the circulatory system, it consists of several components:

- Heart, the primary organ of the circulatory system that maintains blood pressure and controls blood velocity.
- Blood, and its sub-components

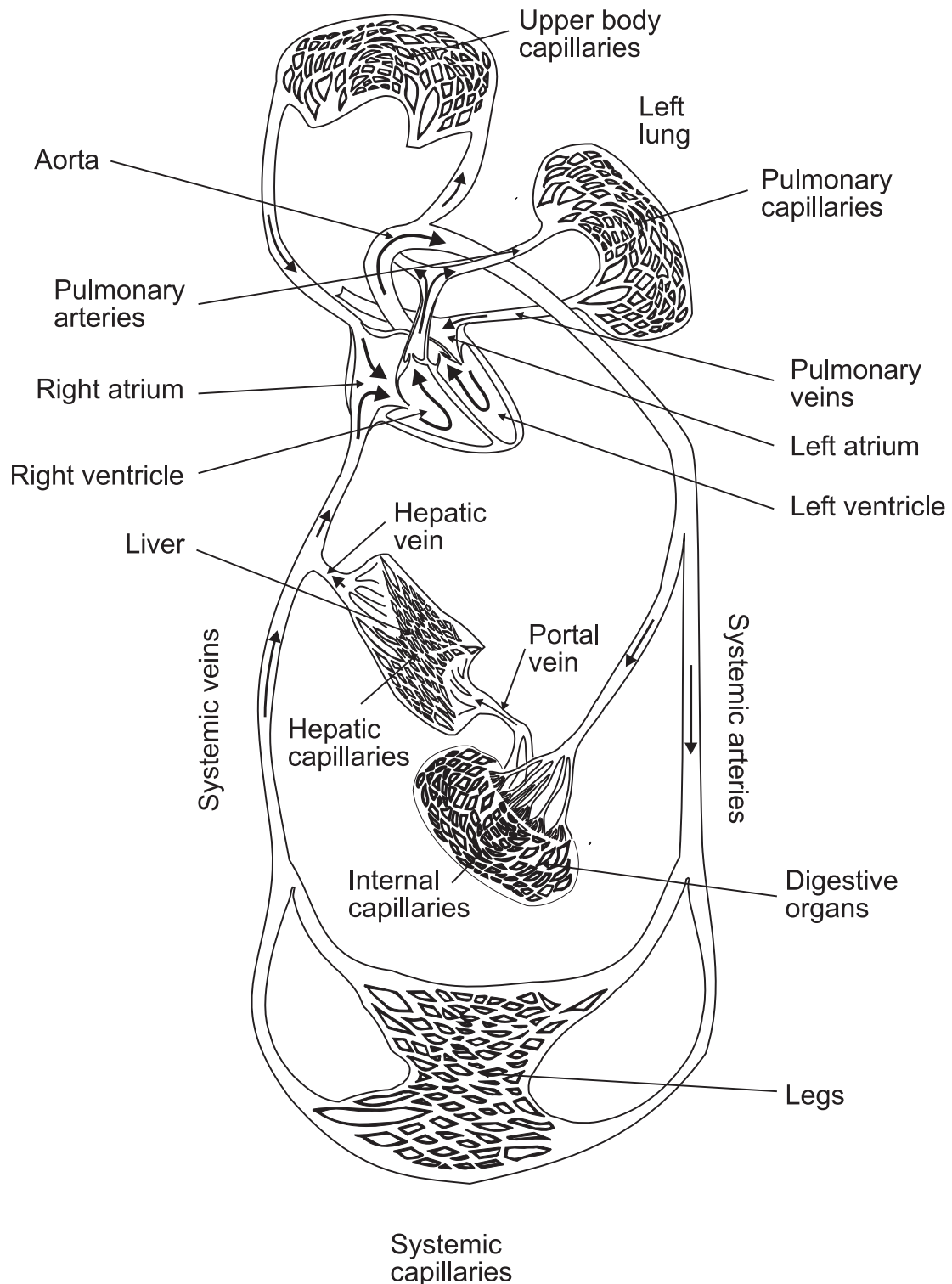


Figure 2.5: Circulatory system of the human body [19]

- Plasma, which forms the primary volume and contains nutrients and formed cellular elements.
- Red and white blood cells, which carry oxygen and fight off infections, respectively.

- Platelets, which are also known as thrombocytes, have the function of clotting during blood vessel injury.
- Blood vessels
 - Arteries (and arterioles), transport oxygenised blood to organs and tissues at high pressure and velocity.
 - Capillaries are thin but wide-ranging blood vessels that perform the exchange of matter between the circulatory system and tissue.
 - Veins (and venules) carry blood back to the heart at low pressure and velocity.

2.2.1 Blood flow

Blood flow is the amount of blood that goes through a blood vessel in a particular period of time, and has a complicated flow pattern due to its pulsing flow. Advanced analysis of haemodynamics is not within the scope of this report, so the explanation will be brief. The primary forces that determine the blood flow F are the pressure difference across a blood vessel and vascular resistance. It is determined by Ohm's law as in eq. (2.16).

$$F = \frac{\Delta P}{R} \quad (2.16)$$

Where ΔP is the pressure difference across the blood vessel and R is the vascular resistance. The pressure difference ΔP is calculated with eq. (2.17).

$$\Delta P = P_1 - P_2 \quad (2.17)$$

Where P_1 and P_2 are the blood pressures measured at each end of the blood vessel. Pressure has a significant importance on blood flow because an increase in arterial pressure not only increases the force that pushes blood through the capillaries but also expands the vessels, lowering vascular resistance.

2.3 Devices

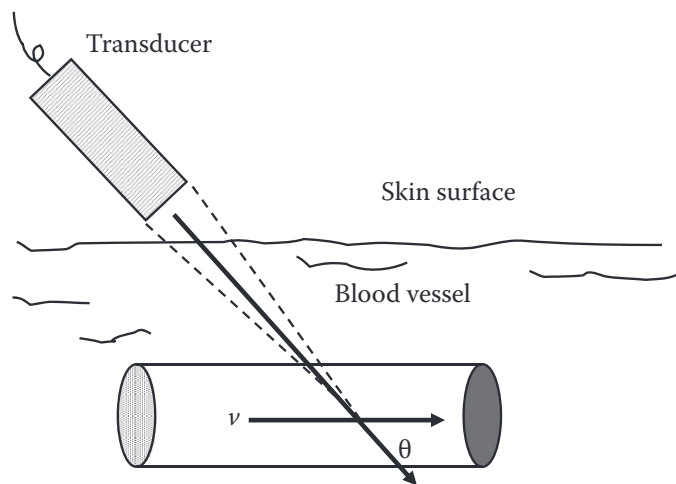


Figure 2.6: Diagram of *US* wave transmitted and reaching blood vessel with incident angle θ [21]

A device that measures the flowing of blood is called a flowmeter. Flowmeters may be used both inside and outside of vessels. One of the flowmeters that may be used outside

the vessel to monitor flow is *US*. Figure 2.6 depicts an ultrasonic wave of frequency f insonifying a blood artery, resulting in an angle of θ relative to velocity v . For simplicity, it is assumed that blood flows in a vessel at a constant velocity v . The echoes returned are shifted in frequency as described in eq. (2.15) earlier in the chapter. The echoes scattered by blood after being insonified by an ultrasonic wave convey information about the velocity of blood flow. Blood flow measurements are often used in clinical settings to determine the status of blood vessels and organ functioning. The two commonly used fundamental techniques for ultrasound Doppler flow measurements are continuous-wave (*CW*) and pulsed-wave (*PW*). Both will be explained.

2.3.1 Continuous-wave Flowmeter

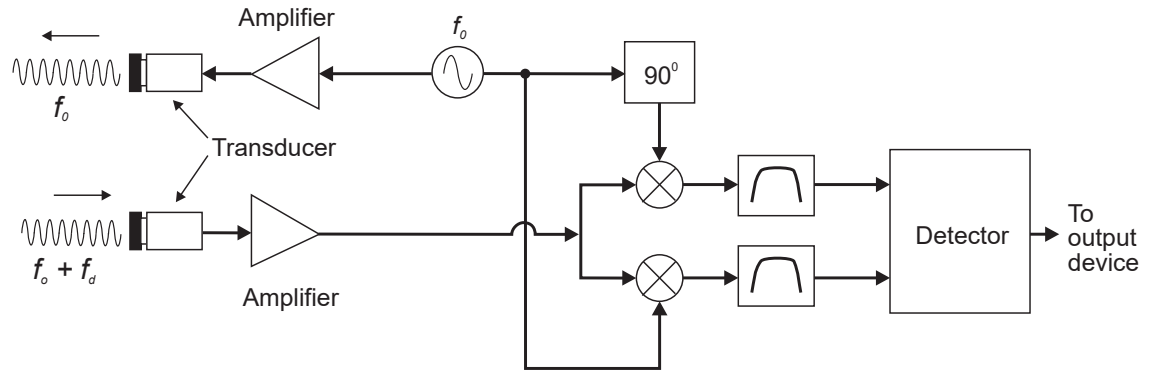


Figure 2.7: Block diagram of *CW* flowmeter [19]

The earliest non-invasive cardiovascular diagnostic technologies relied heavily on *CW* Doppler flowmeters. One of the earliest concepts for a device to estimate and study blood flow was proposed by Satomura, Yoshida, Mori, *et al.*[1] during the 1950s in Japan. To continuously transmit waves and receive signals from moving reflectors, the *CW* flowmeter uses two transducers. *CW* flowmeters use less sophisticated electronics than *PW* flowmeters. A drawback to the *CW* flowmeter is the lacking depth discrimination due to the continuous characteristic of this device type. A block diagram of a typical *CW* flowmeter can be seen in fig. 2.7. The basic principles of the device are previously explained in section 2.1.4, and the measurement of the device is described in eq. (2.11). The device continuously emits an ultrasonic wave in the first transducer expressed as a function of time by eq. (2.18) [19].

$$e(t) = \cos(2\pi f_0 t) \quad (2.18)$$

While receiving the backscattered signal on the second transducer expressed by eq. (2.19) [19].

$$r_s(t) = a \cos(2\pi f_0 \alpha(t - t_0)) \quad (2.19)$$

$$\alpha \approx 1 - \frac{2v_z}{c} \quad (2.20)$$

$$\alpha t_0 \approx \frac{2d_0}{c} \quad (2.21)$$

Where v_z indicates the velocity in the z direction. Applying the Fourier transform, the expression yields eq. (2.22).

$$r_s(t) \cdot e^{j2\pi f_0 t} \Longleftrightarrow R_s(f - f_0) \quad (2.22)$$

Where $R_s(f - f_0)$ is the Fourier transform of $r_s(t)$. The received signal is then multiplied with a quadrature signal of frequency f_0 to find the Doppler frequency in eq. (2.23).

$$m(t) = a [\cos(2\pi f_0 t) + j \sin(2\pi f_0 t)] \cos(2\pi f_0 \alpha(t - t_0)) \quad (2.23)$$

$$= \frac{a}{2} \left\{ \cos(2\pi f_0 [(1 - \alpha)t - \alpha t_0]) + \cos(2\pi f_0 [(1 + \alpha)t - \alpha t_0]) \right. \\ \left. + j \sin(2\pi f_0 [(1 - \alpha)t - \alpha t_0]) + j \sin(2\pi f_0 [(1 + \alpha)t - \alpha t_0]) \right\} \quad (2.24)$$

As is general for quadrature demodulation, the resulting signal contains the frequency components of the sum and difference of the emitted and received signals' frequencies shown in fig. 2.8, where the signals are shown in time and frequency domains.

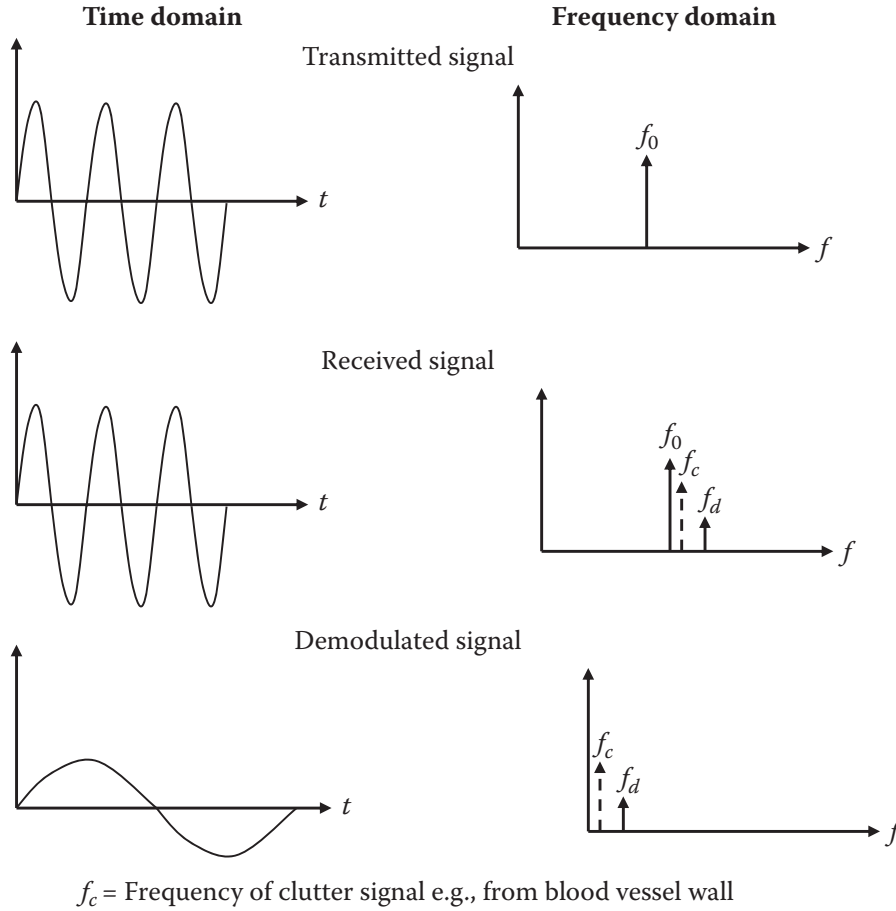


Figure 2.8: Doppler signals in time and frequency domain showing demodulation effects [21]

Generally, a band-pass (*BP*) filter is used on the demodulated signal to remove the high-frequency summed signal at twice the frequency of f_0 . The filtered signal after the *BP* filter is expressed by eq. (2.25) and contains the Doppler shift of the emitted signal.

$$m_f(t) \approx \frac{a}{2} e^{(j2\pi f_0 \frac{2v_z}{c} t)} e^{(-j2\pi f_0 \alpha t_0)} \quad (2.25)$$

Where the second exponential term is the delay proportional to the time between transmission and receiving of the signal. The selected cutoff frequency is chosen to be much lower than the carrier frequency to remove the carrier wave. One issue with ultrasonic Doppler

blood flow monitoring is that the blood vessels that generate large reflected echoes are also moving with a low velocity. These big, slow-moving echoes are referred to as clutter signals in Doppler nomenclature. The band pass filter's low-end cutoff frequency must be designed to minimize interference from these clutter signals. The design of this band pass filter in the low-frequency region, which serves the function of high pass, also known as a clutter rejection filter, has proven troublesome since the magnitude of clutter signals is many orders greater than that of blood and may obfuscate those from slow-moving blood.

Table 2.3: Measured frequency shifts with a Doppler 3 MHz transducer at various velocities at a 45° incident angle [19]

Velocity (v) m/s	Doppler frequency (f_d) Hz
0.01	28
0.1	276
0.5	1377
1	2755
2	5510
5	13 770

Seen in table 2.3 is an example of measured Doppler frequencies using a 3 MHz transducer using the method shown in fig. 2.6. Note that the measured frequencies are all within the audible range.

2.3.2 Pulsed-wave Flowmeter

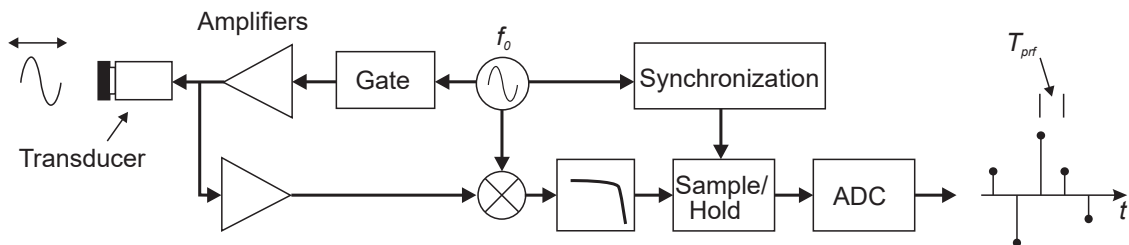


Figure 2.9: Block diagram of *PW* flowmeter [19]

The concept of a pulsed-wave flowmeter was proposed in [2] and other related articles. This type of flowmeter is periodically changing from a transmitter to a receiver. In the transmit mode, the transducer emits a series of pulses. When in the receiving mode, the transducer is listening for the backscattered signal. A simplified block diagram can be seen in fig. 2.9. The movement of particles within the blood causes a displacement in the backscattered signal. These systems are commonly referred to as “Doppler systems” even though it is somewhat misleading. The effects of attenuation are also causing a shift in frequency of a higher magnitude than the velocity of particles in the blood. This is because the conventional Doppler effect is not the straightforward methodology that is applied to the analysis of the back-scattered signal. It is, in fact, an artefact. It is the shift in the location of the scatters that is observed, not the shift in the transmitted frequency. Figure 2.10 shows the received signal after demodulation and filtering; the depth in tissue is fixed here, and the signals displayed on the left side of the figure are the result of a pulse sequence. Each line represents a single pulse, and each pulse is emitted at a pulse

repetition frequency, f_{prf} . Instead, on the right, the dotted line shows the sampled signal formed by taking into account the amplitude of each pulse after a specified time period.

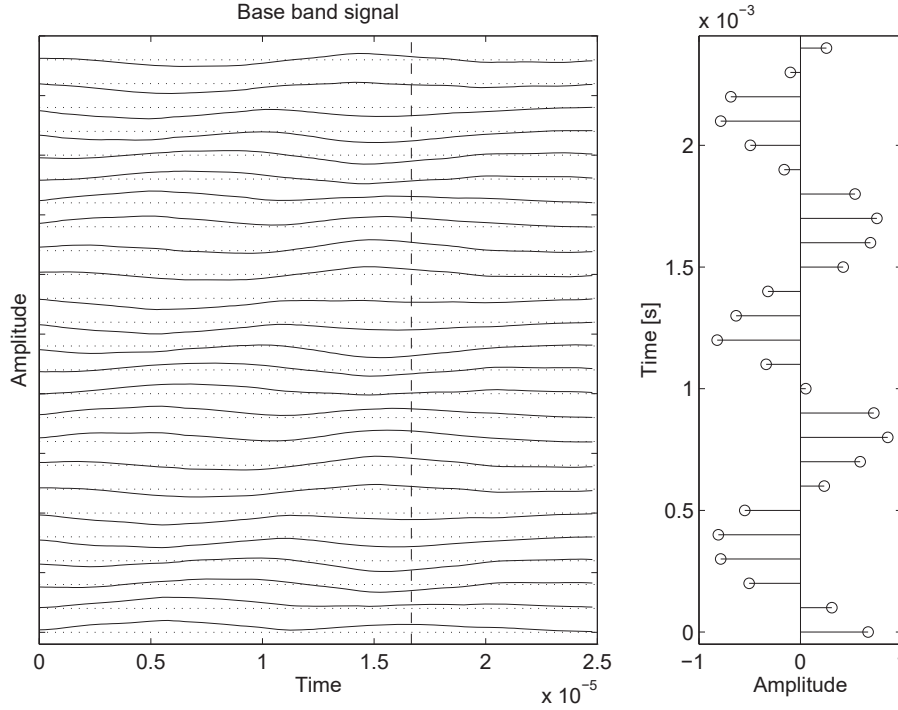


Figure 2.10: Sampling for a gate pulsed wave system with a single range. To depict the signals on the graph, a single pulse is emitted for each line, and the signals are displaced in amplitude. The sampled signal is displayed on the right. [19]

After the back-scattered signal is received it is multiplied by the centre frequency of the emitted pulse and filtered to remove the sum frequency [19]. A analogue-to-digital converter (*ADC*) quantifies the signal for further signal processing. Referring to displacement fig. 2.10 again, the dashed vertical line represents the sample of each pulse that is taken. If sampling is done T_s after pulse emission, the measurement depth is expressed by eq. (2.26).

$$d_0 = \frac{T_s c}{2} \quad (2.26)$$

Hypothetically, if the velocity of stationary scatterers in blood was measured, a constant amplitude would be measured. A change in the sample value is observed when there is movement. Between two pulses, the scatterer movement is proportional to the velocity v_z in the direction of the ultrasound beam. The time shift of t_s is expressed as eq. (2.27).

$$t_s = \frac{2v_z}{c} \cdot T_{\text{prf}} \quad (2.27)$$

Where c is the speed of sound, and T_{prf} is the timespan between each pulse emission. Taking one sample from each line at a certain depth yields a sampled signal with a frequency proportional to the scatter velocity. Thus, if a sample is taken at the same depth for each line, resulting in a sinusoidal signal proportional in frequency to the scatter velocity [7] and that signal is expressed by eqs. (2.28a) and (2.28b).

$$r(i) = a(i) \sin(2\pi f_p T_{\text{prf}} \cdot i) \quad (2.28a)$$

$$f_p = \frac{2v_z}{c} f_0 \quad (2.28b)$$

Where $a(i)$ is the amplitude, f_0 is the emitted frequency, and θ is the phase factor in the depth of interest. This technique improved the accuracy of the investigations of blood vessels and facilitated the display of velocity profiles. Furthermore, by employing two transducers or a multi-element transducer, duplex mode imaging (displaying both a B-mode picture and a blood velocity estimate) became feasible. Two-transducer systems are no longer utilised since it is easier to create a duplex picture with a multi-element transducer.

Hvor er θ i udtrykket?
Omskriv fra Jensen2012

2.4 Blood Velocity Estimation

Once a backscattered signal is received, estimation of velocity can be obtained with multiple methods. In this section the most common methods to estimate blood velocity are mentioned with their strengths and limitations.

2.4.1 Spectral estimation

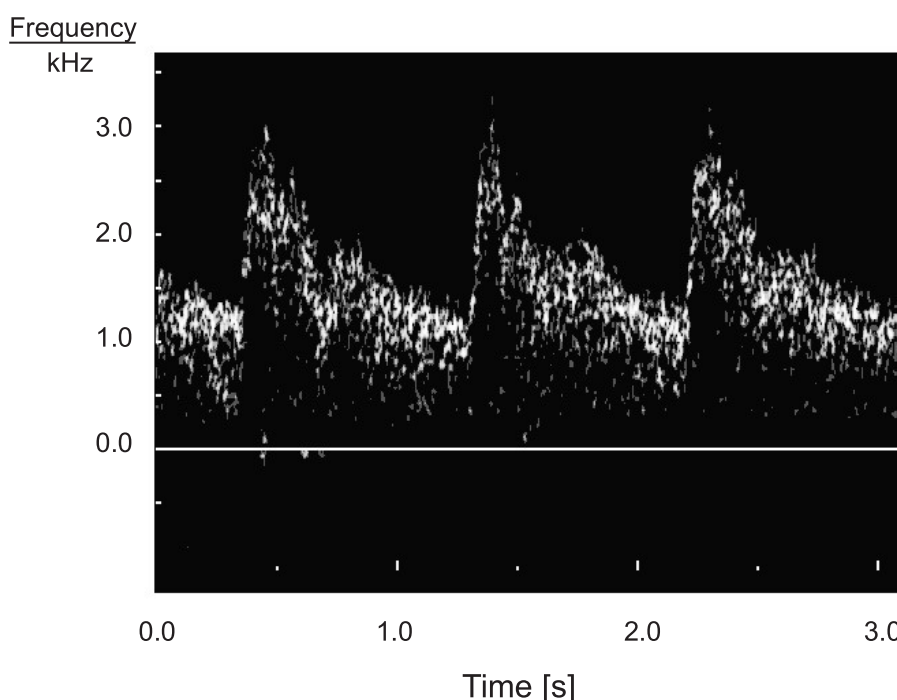


Figure 2.11: Arterial sonogram with time-frequency and Doppler shift [19]

Given that the frequency volume of the received signal is similar to the blood's velocity distribution, the Fourier transform of the received signal can be used to obtain velocity. The spectrogram, usually erroneously known as the Doppler spectrum, can be created by saving the *PSD* together. The *PSD* is calculated for each of the components that make up the received signal in order to accomplish this. A quadrature demodulated signal is used to display both positive and negative frequencies. When these spectra are shown side by side, the evolution of the velocity distribution can then be seen. A sonography of an artery is displayed in fig. 2.11.

3 Synthesis

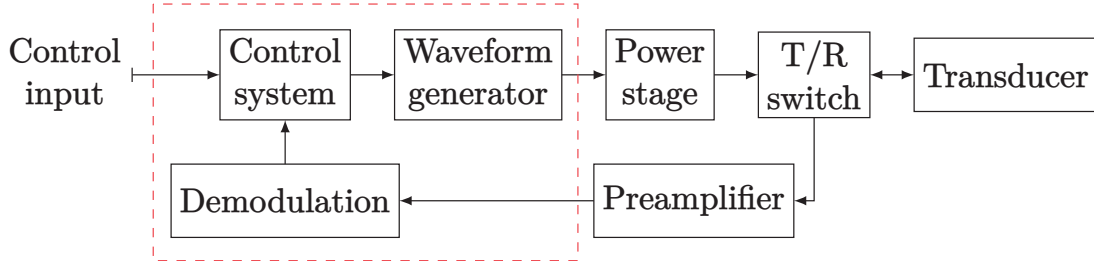


Figure 3.1: Simplified overview of the system with the demodulation and control system indicated with a red dashed rectangle

A simplified overview of the entire system can be seen in fig. 3.1. Each of the various modules will be explained during this chapter of the report. Initially, the control system will be briefly explained and the reasons for its design choice. Secondly, the signal chain in the transmitter will be outlined and how the transducer is driven by the power stage with the added protective switching circuit. Finally, the analogue front-end will be further explained with its various subcircuits for amplifying and demodulating the signal. Lastly, the design of the digital signal processor (*DSP*) within the control system will be explained.

3.1 Control System

The choice of platform for the control system is a microcontroller. A microcontroller is a small computer that is built into a single integrated circuit (*IC*) chip. It includes a central processing unit (*CPU*), memory, and input/output (*I/O*) peripherals, and it is designed to perform a specific set of tasks. Microcontrollers are used in a wide range of electronic devices, including appliances, automobiles, industrial control systems, and consumer electronics. Microcontrollers are often used in applications where a small, low-power device is needed to perform simple tasks, such as controlling a motor or reading a sensor. They are usually programmed in a high-level language, such as C or C++, and they can be programmed to perform a variety of tasks, depending on the specific application. The chosen microcontroller unit (*MCU*) for this project is STM32F411RE, because it is sufficient for the application and sourcing limitations within the *IC* supply chain. In addition, the selected development environment was Visual Studio Code with PlatformIO and Zephyr RTOS. Both are explained in the following subsections.

3.1.1 PlatformIO

PlatformIO is an open-source ecosystem for embedded development. It is designed to help developers build applications for various microcontrollers, such as Arduino, Raspberry Pi, and others. PlatformIO is available as a plugin for many popular integrated development environments (IDEs), including Visual Studio Code, Atom, and CLion. PlatformIO manages the project dependencies, builds and uploads code to microcontrollers, and debugs the applications. It also includes a library manager, which allows developers to easily include and manage external libraries and frameworks in their projects. PlatformIO is a cross-platform tool, which means it can be used on various operating systems, including Windows, macOS, and Linux. It is a popular choice for embedded development because of its ease of use and powerful features. PlatformIO works by downloading and setting

up a set of tools and libraries that allows building, uploading, and debugging various microcontrollers. It includes a library manager, a build system, and a debugger, as well as support for a wide range of microcontrollers and development boards. To use PlatformIO, it is installed as an extension to the preferred integrated development environment (IDE) Visual Studio Code. Then, a new PlatformIO project can then be created by selecting the desired microcontroller and development board, and specifying any external libraries or frameworks they need to include. In this case, Zephyr RTOS is used as a framework. PlatformIO's build system takes care of compiling the code and linking it with any required libraries or frameworks. The debugger allows for stepping through the code and inspecting variables, setting breakpoints, and troubleshooting bugs.

3.1.2 Zephyr

Zephyr is an open-source real-time operating system (*RTOS*) designed for the Internet of Things (IoT). It is a lightweight RTOS that can run on a wide range of devices, from microcontrollers with as little as 20 KB of RAM to more powerful systems with multiple processors. Zephyr is designed to be modular and scalable, with a focus on security and low power consumption. It includes support for a wide range of hardware architectures, including ARM Cortex-M, x86, and RISC-V, and it can be used with a variety of development boards and microcontrollers. One of the key features of Zephyr is its ability to run on very small devices with limited resources. It includes support for various networking protocols, such as Bluetooth Low Energy (BLE), IPv4, and IPv6, which makes it well-suited for use in IoT applications. Zephyr is developed as part of the Linux Foundation's Zephyr Project, and it is widely used in the development of IoT and embedded systems. It is a popular choice for lightweight, flexible, and secure RTOS projects.

Real-Time Operating Systems

A real-time operating system is an operating system that is designed to handle real-time applications. Real-time applications are those that require timely processing of data in order to function correctly. This can include tasks such as controlling industrial machinery, monitoring and controlling processes. Real-time operating systems are designed to prioritize certain tasks and ensure that they are completed within a specific timeframe. They do this by allocating a certain amount of processing resources to each task, and by interrupting the execution of lower-priority tasks as needed to ensure that high-priority tasks are completed on time. RTOSs typically include features such as preemptive scheduling, real-time communication, and support for multiple processors and hardware architectures.

3.2 Pulse-Width-Modulation Generator

Initially, a waveform generator was designed by using a programmable synthesizer circuit, but due to constraints within generating dead-time when driving the half-bridge, a more accurate timer based PWM generation is required. In a half-bridge power stage, dead-time refers to the amount of time that elapses between the moment when one of the switches in the half-bridge (either the high-side or the low-side switch) turns off and the moment when the other switch turns on. During the dead-time, both switches in the half-bridge are off, which means that there is no current flowing through either switch in the half-bridge. A scenario where both switches are on, can cause problems if the output of the half-bridge is connected to a load, as it may cause the load to behave erratically or even be damaged. To avoid these problems, it is important to carefully consider the amount of dead-time in a half-bridge power stage. In general, a longer dead-time will reduce the risk of damage to the load, but it will also reduce the efficiency of the power stage, as energy will be lost

during the dead-time. Therefore, the designer must carefully balance the trade-off between efficiency and safety in order to determine the optimal amount of dead-time for a given half-bridge power stage. A complementary timer

3.3 Power Stage

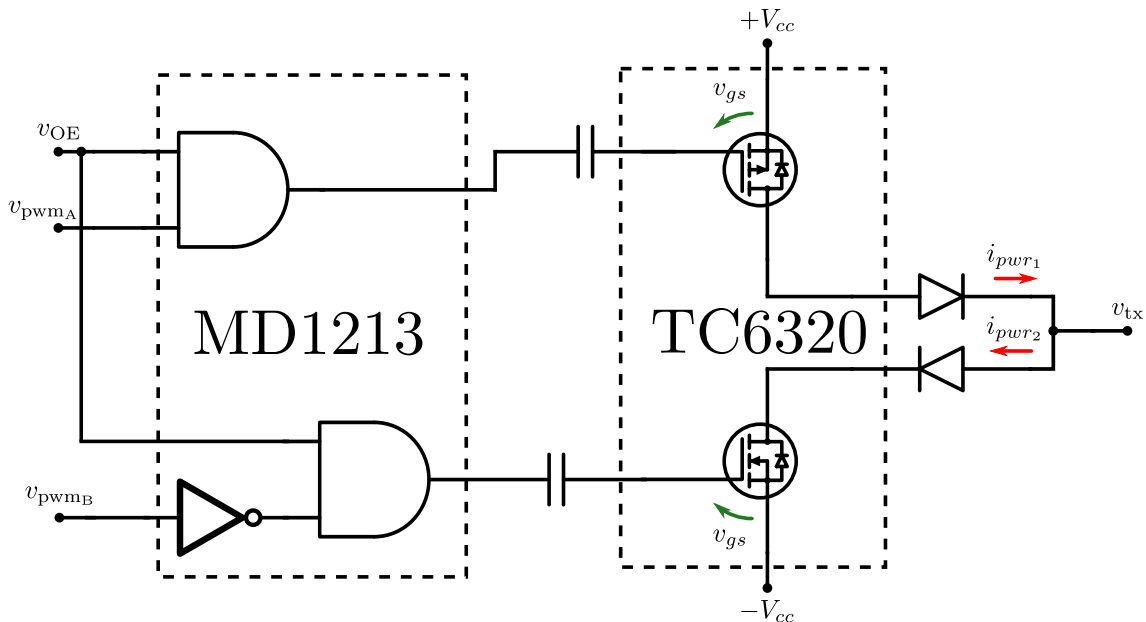


Figure 3.2: Circuit diagram of power stage

Gate drivers [10], [26], [31]

3.4 Transmit/Receive Switch

The transmit/receive switch is a module that is based on an IC from Texas Instruments known as TX810. The TX810 is an electronic device that can be used to switch transmit and receive paths of an ultrasound system. It can switch the transmit and receive paths for up to 8 different transducers (also known as probes) at the same time. The TX810 is programmed to switch the transmit and receive paths at specific times, as determined by the user. For example, the user can program the TX810 to switch the transmit and receive paths of a particular transducer at a specific time during the ultrasound examination. This allows the user to perform multi-channel imaging, where multiple transducers are used simultaneously to capture images from different angles. The IC is typically used in conjunction with an ultrasound system and one or more transducers. Transducers are used to transmit and receive ultrasound waves, which are used to generate images of the body's internal structures. The TX810 is used to switch the transmit and receive paths for each transducer at the appropriate times, allowing the ultrasound system to capture images from multiple angles simultaneously. When high-voltage transmitter signals are applied to the input, the internal diodes limit the output voltage. While in receive mode, the TX810's insertion loss is minimized. The TX810 features a 3-bit interface that may be used to program bias current from 7 mA to 0 mA for varying performance and power requirements, unlike conventional T/R switches. The device is put up in power-down mode when the TX810 bias current is set to 0mA (high-impedance mode). The TX810 does not put significant load on high-voltage transmitters when operating in the high-impedance

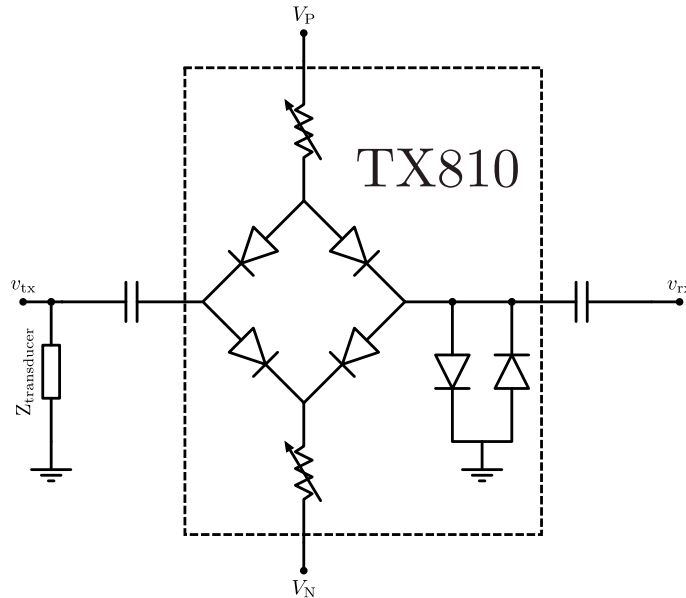


Figure 3.3: Circuit diagram of switch (per channel)

mode. The device can also wake up from power-down mode in less than a μ s. These sophisticated programmable features enable systems to save a large amount of electricity.

The module is designed with three channels available. That means three channels can be used, either three separate transducers for multi-angle sonography, or a capacitive micromachined ultrasound transducer (*CMUT*) with three channels in a single angle.

3.5 Transducer

3.5.1 Impedance matching input

3.6 Preamplifier

OPA487

The OPA847[12] is a high-performance, high-speed, voltage feedback amplifier with a bandwidth of over 1 GHz. It has a wide gain range, low distortion, and low noise, making it suitable for a variety of applications including video, RF, and high-speed data acquisition. The OPA847 has a single-ended input and a differential output, which allows it to be used in a variety of circuit configurations. It is available in a surface-mount package and operates over a wide supply voltage range.

AD8332

The AD8332[22] is a fully integrated, single-chip amplifier designed for use in a wide range of RF and microwave applications. It is a low-noise, high-linearity amplifier that can be used in a variety of configurations, including as a stand-alone amplifier or as part of a larger system. The AD8332 is a current-feedback amplifier that can operate over a wide frequency range, from 50 MHz to 4 GHz. It has a high level of integration, with all active components on a single monolithic IC. This makes it suitable for use in small form factor applications where space is at a premium. The AD8332 has a number of features that make it well-suited for use in RF and microwave applications. It has a high level of linearity, which allows it to amplify signals without introducing significant distortion. It also has a low noise figure, which makes it well-suited for use in low-noise applications. Additionally, the AD8332 has a wide dynamic range, which makes it capable of handling a wide range

of input signals without clipping or saturating. Overall, the AD8332 is a versatile and reliable amplifier that can be used in a wide range of RF and microwave applications. It is well-suited for use in a variety of systems, including communication systems, radar systems, and instrumentation systems.

3.7 Demodulation

To demodulate our signal using the process described in The AD8333[23] is an integrated circuit (IC) that can be used to demodulate an amplitude-modulated (AM) signal. It contains all the necessary circuitry to detect and extract the information contained in an AM signal. In AM, the information is encoded in the amplitude of the carrier wave, which is modulated or varied in some way to convey the information. The AD8333 is able to detect these variations in the carrier wave and extract the original information from the signal. To do this, the AD8333 uses a process called envelope detection. It rectifies the input signal, which removes the negative portions of the waveform, and then filters the resulting signal to remove any remaining high-frequency components. This leaves only the envelope of the original modulated signal, which contains the encoded information. The AD8333 also includes amplifier and buffer stages to amplify the detected envelope and prepare it for further processing or application. It is often used in radio communication systems, industrial control systems, and other applications where an AM signal needs to be demodulated and the information contained in the signal needs to be extracted. Test af git push.

3.8 Sample/Hold

3.9 Pulse-Repetition and Wall Filter

3.10 Amplifier

3.11 Mixer

3.12 Adder

4 Production

In the following a bunch of examples of figures and tables have been made. There are advantages to using `tikZ` diagrams over excel diagrams. 1) the font and font size perfectly matches the document 2) the styling and colours are pre-defined to follow the design guide 3) the plots uses vector graphics which reduces the file size, reduces the compile time and looks sharp when zooming in. The possibilities are endless, look at the `pgfplots` gallery for inspiration: <http://pgfplots.sourceforge.net/gallery.html>. However there are still cases where I would recommend to insert a plot as a picture. For example if the plot contains a lot of data: a line graph with 1000 points takes a long time to compile.

Some tips if you want good looking diagrams or graphs which will be inserted as pictures (e.g. in a figure environment with `\includegraphics`): The main font is Arial. Use DTU colours as described in ???. Use high quality pictures. Try to scale the diagram (picture) so the text size of the axis legends match the text size in this document.

Remember to change the label of your figures so there are no duplicate labels. A label should be placed below a caption or after a heading (fx after a `\chapter`).

4.1 Graphs and charts

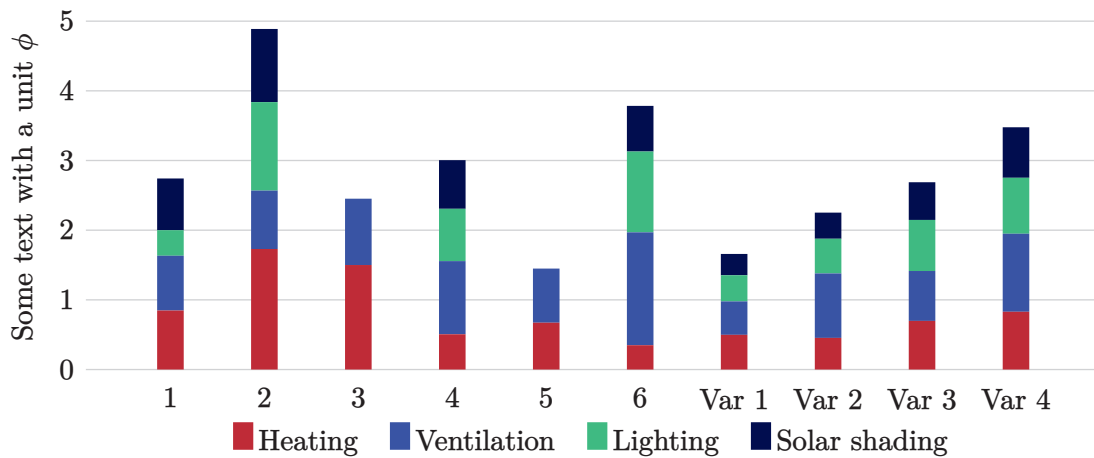


Figure 4.1: Stacked column chart

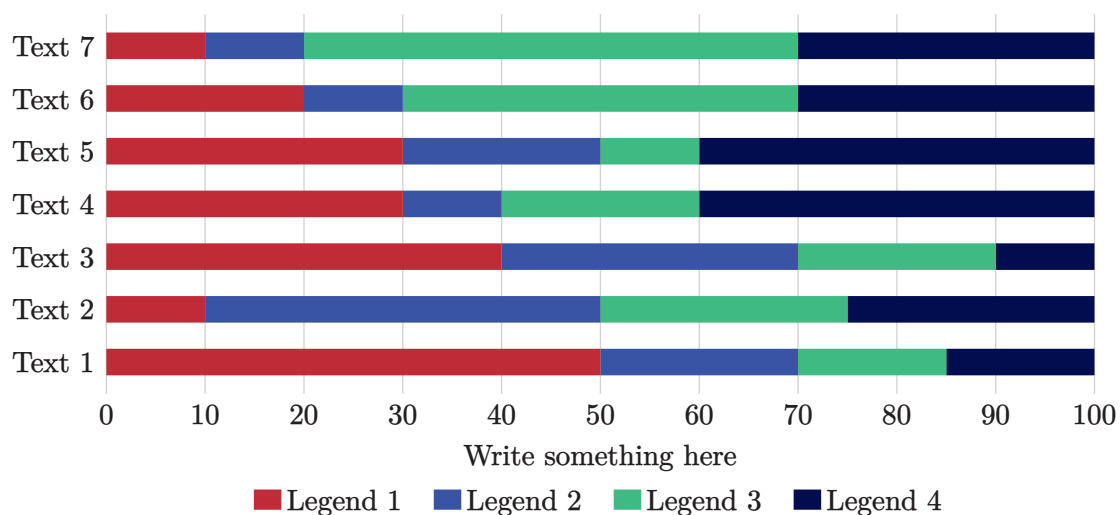


Figure 4.2: Stacked bar chart

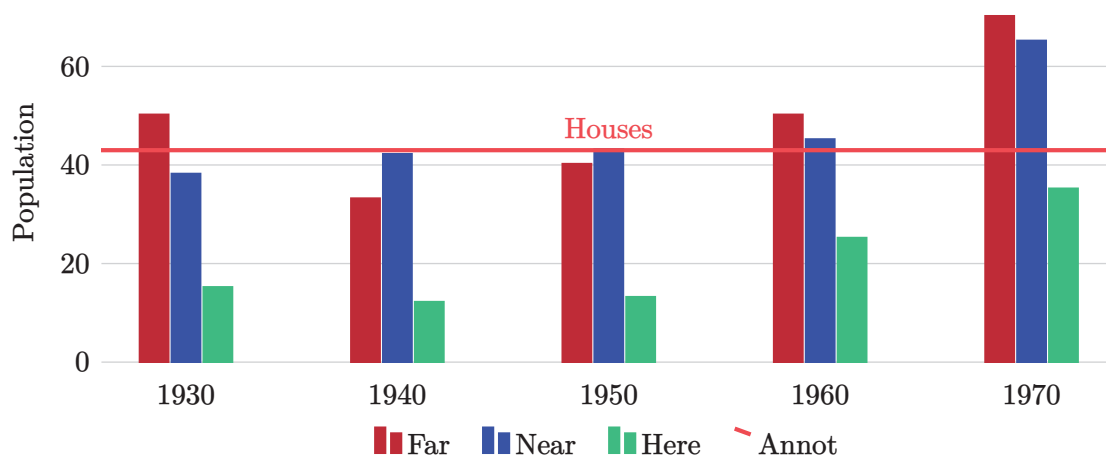


Figure 4.3: Grouped column chart

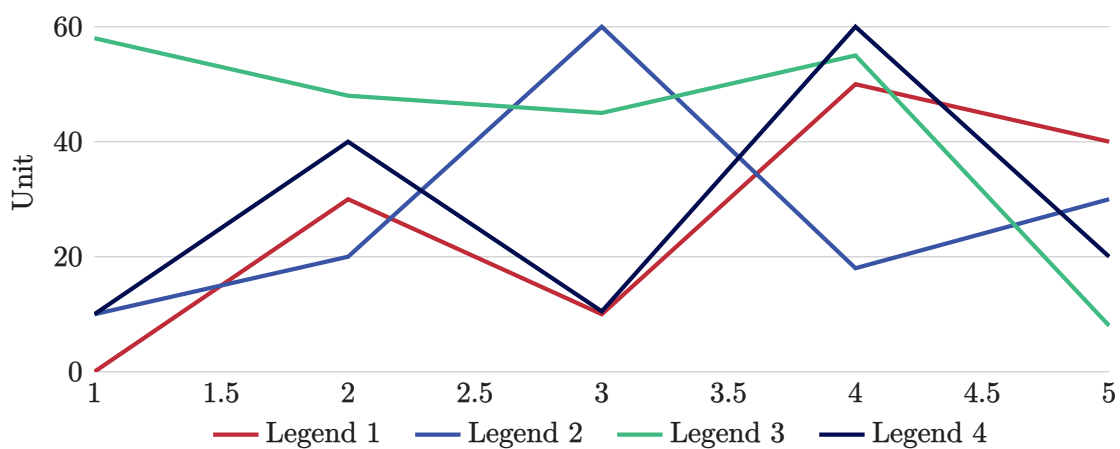


Figure 4.4: Line graph

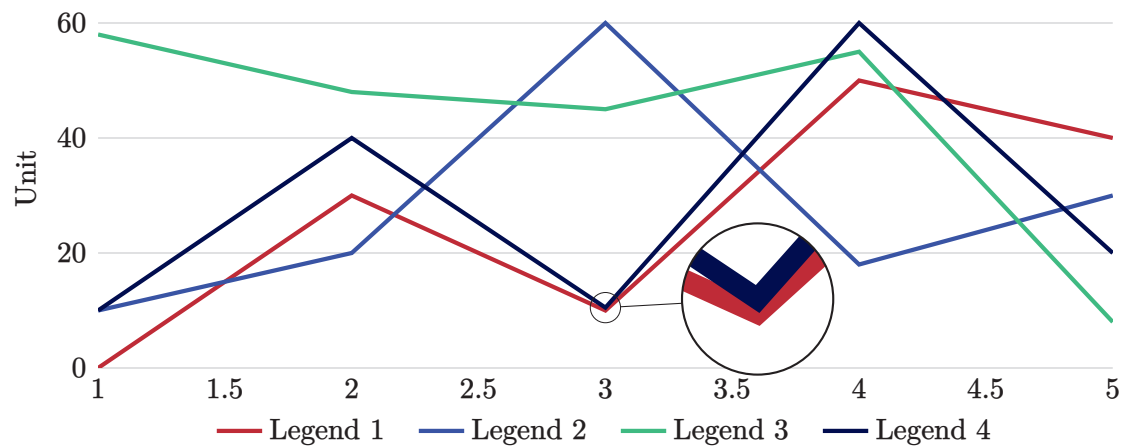


Figure 4.5: Line graph with magnifying glass

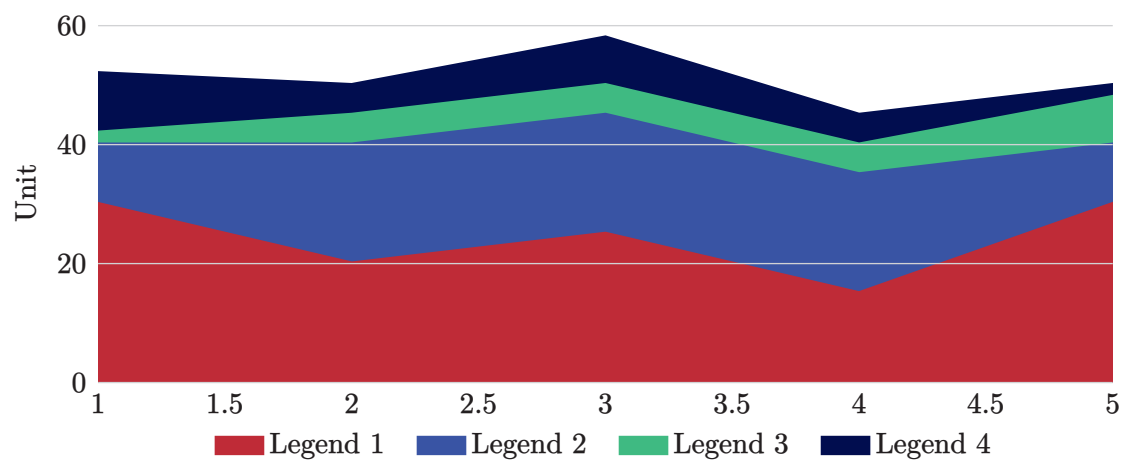


Figure 4.6: Area graph

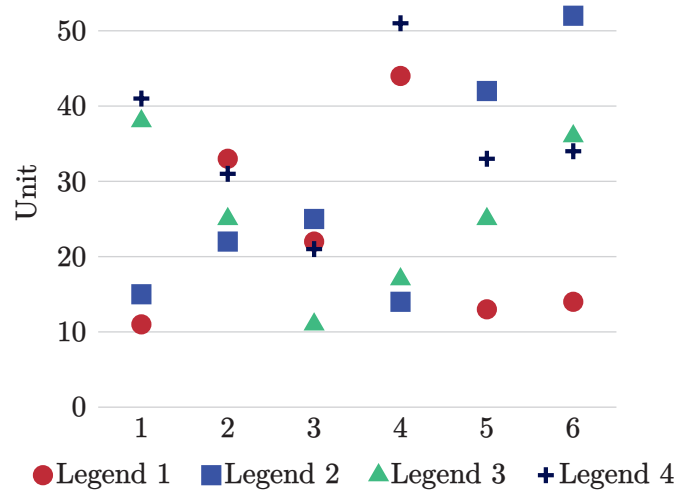


Figure 4.7: Scatter plot

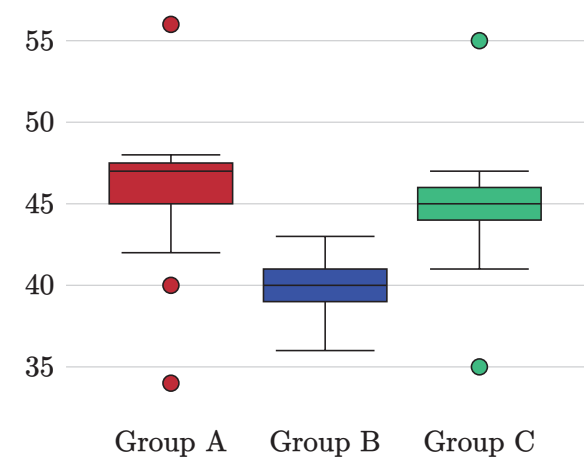


Figure 4.8: Boxplot

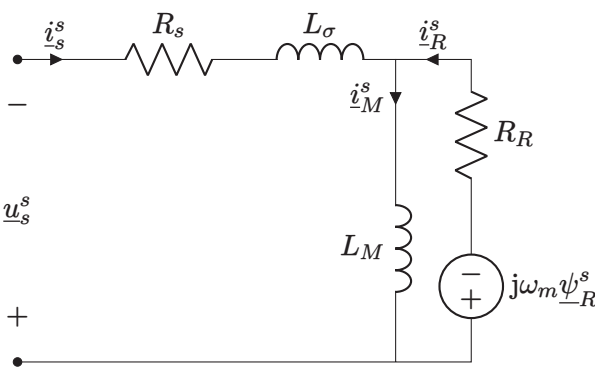


Figure 4.9: The nodes short, V, R and L are presented here, but there a lot more

4.2 Tables and figures

Table 4.1: This is a `booktabs` table

Animal	Description	Price (\$)
Gnat	per gram	13.65
	each	0.01
Gnu	stuffed	92.50
Emu	stuffed	33.33
Armadillo	frozen	8.99

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Table 4.2: Wrongly formatted table

	Voltage V	Current A	Power W
Transformer input	234.4	0.50	117.4
Transformer output	25.86	2.72	70.3
Efficiency			60%

Table 4.3: Correctly formatted table

	Voltage V	Current A	Power W
Transformer input	234.4	0.50	117.4
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Efficiency			60 %

Table 5.2 and table 5.3 have the same contents but there are some subtle differences in formatting which makes table 5.3 the superior table of the two. The most obvious change is removing the midrule between the transformer input and output rows. The efficiency row is the odd man out and a midrule has been used to emphasise the difference between the transformer rows and the efficiency row. The delimiters in the voltage, current and power columns are aligned. The horizontal lines (rules) fits to the content and instead of protruding. The spacing between 60 and the percentage sign is correctly adjusted.



Figure 4.10: Just a normal figure



(a) A subfigure



(b) A subfigure

Figure 4.11: A figure with two subfigures



(a) A subfigure



(b) A subfigure



(c) A subfigure



(d) A subfigure

Figure 4.12: A figure with four subfigures

Referring to the figure as a whole fig. 5.12 or to an individual sub figure fig. 5.12a is done the normal way with `\cref{}` commands.

4.3 Equations

In-line math is easy. Anything surrounded by dollar signs becomes a math field. Here is an example: $f(x) = 2x - 1$. Also anything inside the “`\begin{equation}`” and “`\end{equation}`” environment is also a math field. Examples are shown below.

All equations use the default latex font. Some might say it looks weird with a serif font for equations and a sans-serif font for the body text. However, it is very unpractical to change the math font in latex which is the exactly the reason why this has not been done. One benefit of the serif style math font is the clear distinction between symbols (variables) and units.

On the subject of units, those are all taken care of by the `\siunitx` package. Whenever there is a number followed by a unit one should write `\SI{number}{unit}`. Note this

command is case sensitive. If a unit should follow a variable use the command `\si{unit}` (also case sensitive).

The ideal gas law is shown in eq. (5.1).

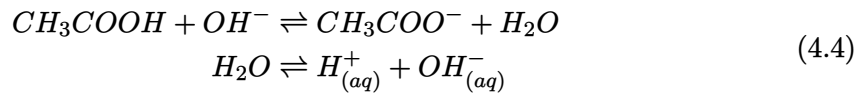
$$p \cdot V = n \cdot R \cdot T \quad (4.1)$$

$$\frac{\partial}{\partial t} \int_0^\delta U dy = -\delta \frac{1}{\rho} \frac{\partial P}{\partial x} - U_f(t)^2 \quad (4.2)$$

$$d_{step} = \sqrt{\frac{\delta}{\frac{dw}{dp_v}} \cdot t} = \sqrt{\frac{1 \text{ kg}/(\text{msPa})}{\frac{5.4 \text{ kg}/\text{m}^3}{233.82 \text{ Pa}}} \cdot 7200 \text{ s}} = 0.001766 \text{ m} = 1.766 \text{ mm} \quad (4.3)$$

$$x = \mathfrak{x}, \mathbf{x}, x, x_{1234}^{1234} \cdot \textit{hello} * \textit{hello world} \cdot \textit{equation without number}$$

Notice how the `aligned` environment can be used to align the equilibrium arrows in eq. (5.4). Only one equation number is generated using this method. Alternatively if you want an equation number for each line see eqs. (5.5) to (5.6).



$$f(x) = 1 + x - 3x^2 \quad (4.5)$$

$$g(x) + y = 3x - \frac{1}{2}x^3 \quad (4.6)$$

4.4 Listings (code)

Listing 5.1 is a nicely formatted block of code. A listing will automatically continue on the next page if it encounters a page break. Many different programming languages can be highlighted. Check the `listings` package documentation for a list of supported programming languages.

```

1  %% Monte Carlo simulation, estimation of pi
2  m=1E7;
3
4  x=rand(m,1);
5  y=rand(m,1);
6
7  g = x.^2+y.^2-1;
8
9  %dots outside
10 Pf = sum((g)<=0)/m
11
12 pi = 4*Pf

```

Listing 4.1: Monte Carlo simulation to estimate the value of π

5 Examples of figures, tables, equations and listings

In the following a bunch of examples of figures and tables have been made. There are advantages to using `tikZ` diagrams over excel diagrams. 1) the font and font size perfectly matches the document 2) the styling and colours are pre-defined to follow the design guide 3) the plots uses vector graphics which reduces the file size, reduces the compile time and looks sharp when zooming in. The possibilities are endless, look at the `pgfplots` gallery for inspiration: <http://pgfplots.sourceforge.net/gallery.html>. However there are still cases where I would recommend to insert a plot as a picture. For example if the plot contains a lot of data: a line graph with 1000 points takes a long time to compile.

Some tips if you want good looking diagrams or graphs which will be inserted as pictures (e.g. in a figure environment with `\includegraphics`): The main font is Arial. Use DTU colours as described in `??`. Use high quality pictures. Try to scale the diagram (picture) so the text size of the axis legends match the text size in this document.

Remember to change the label of your figures so there are no duplicate labels. A label should be placed below a caption or after a heading (fx after a `\chapter`).

5.1 Graphs and charts

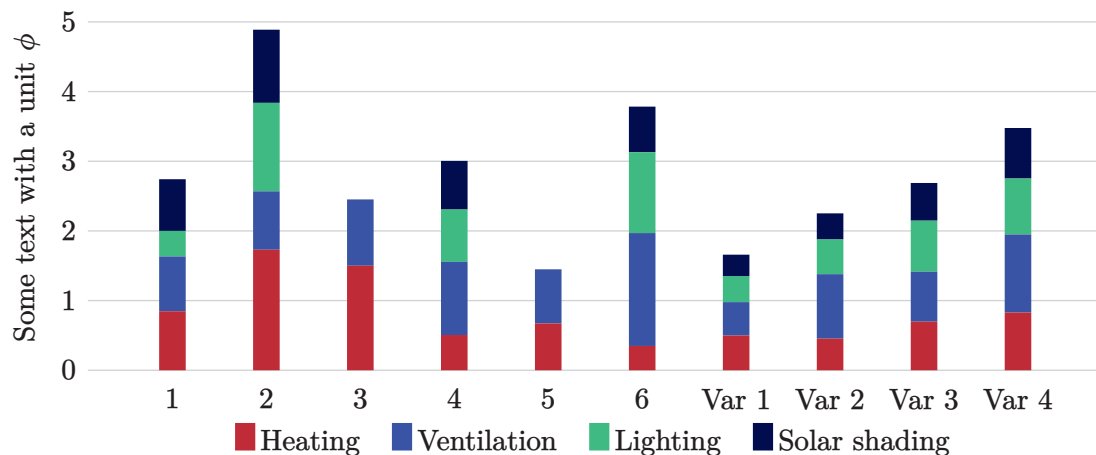


Figure 5.1: Stacked column chart

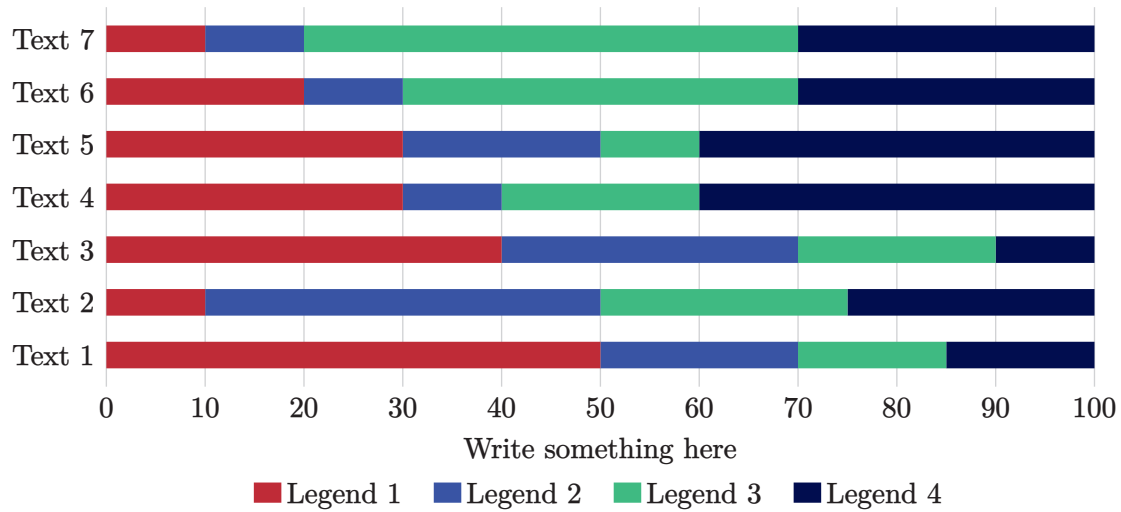


Figure 5.2: Stacked bar chart

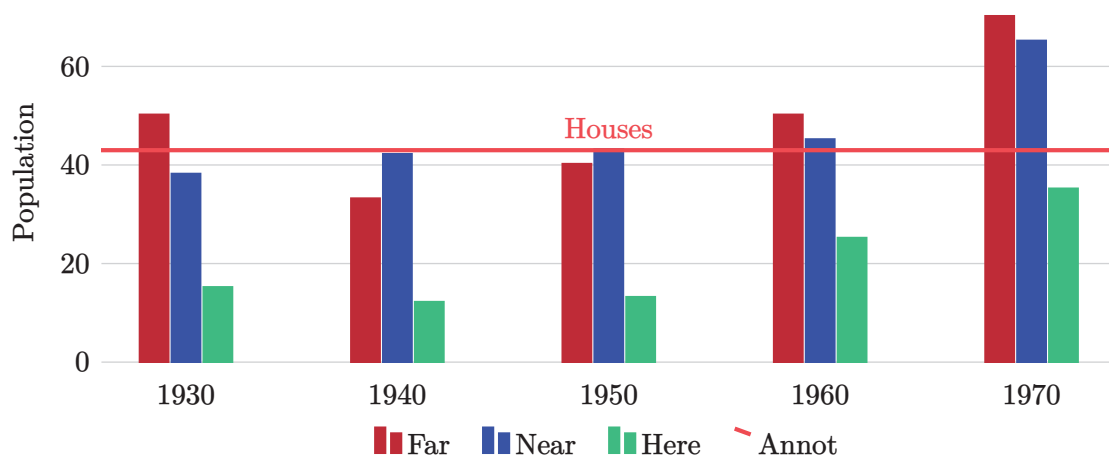


Figure 5.3: Grouped column chart

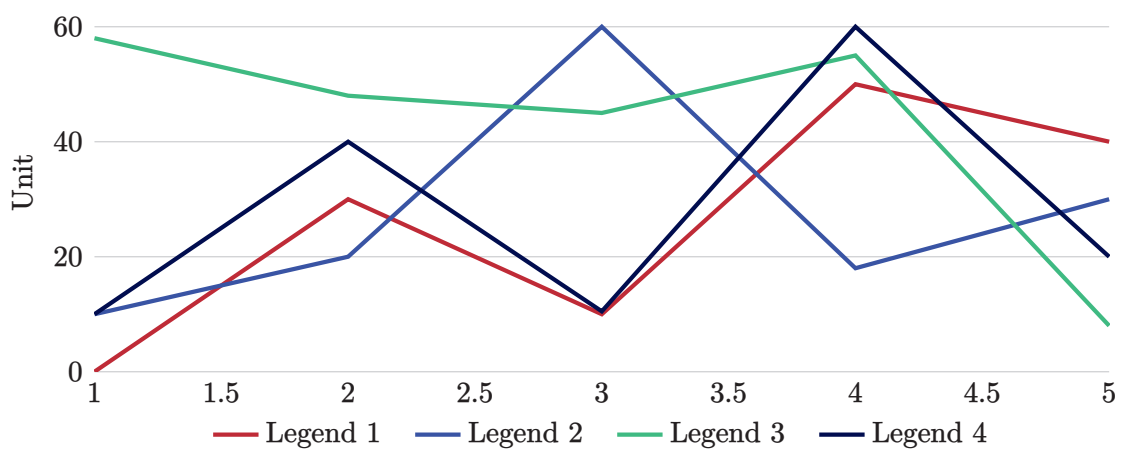


Figure 5.4: Line graph

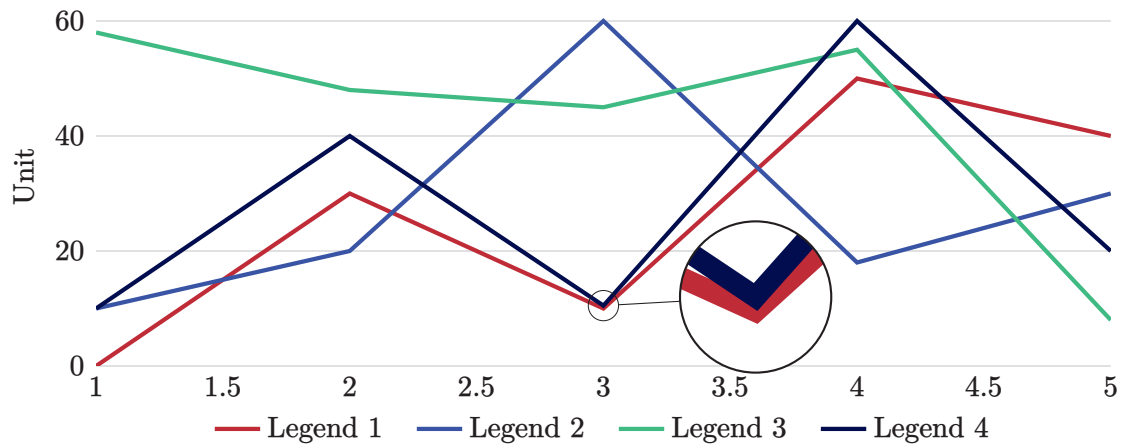


Figure 5.5: Line graph with magnifying glass

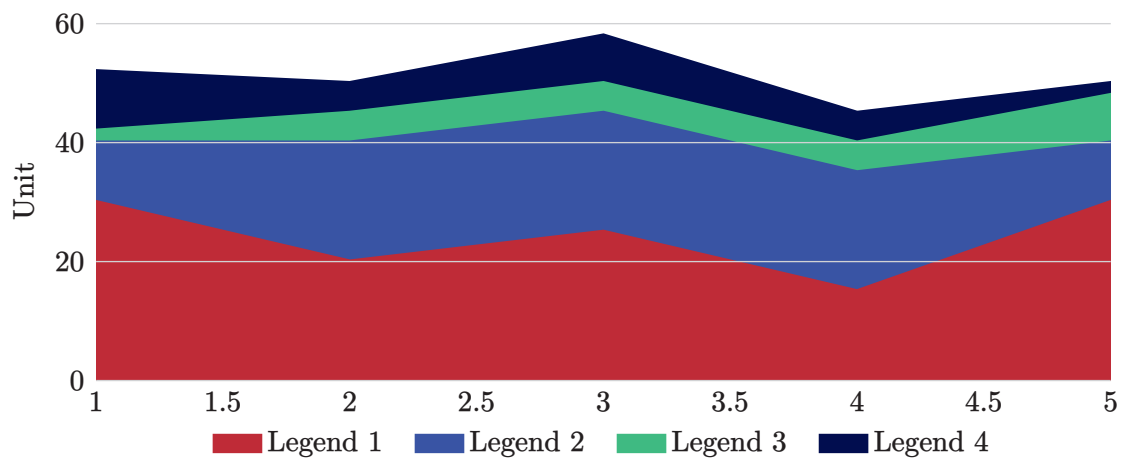


Figure 5.6: Area graph

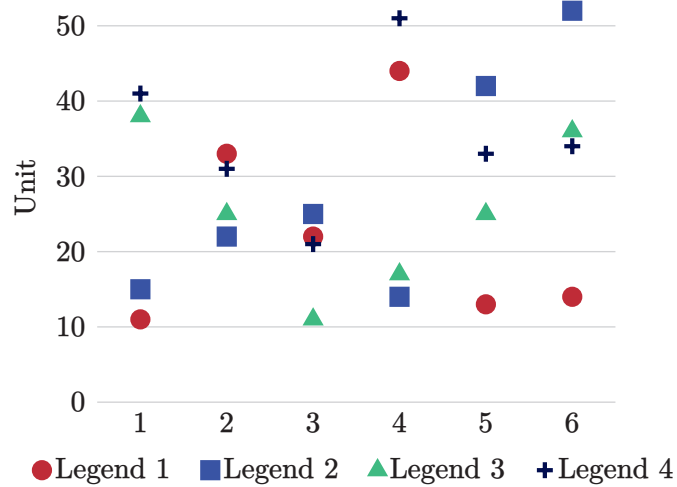


Figure 5.7: Scatter plot

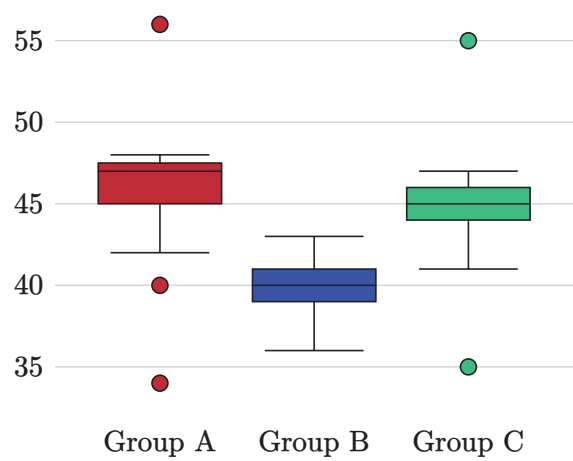


Figure 5.8: Boxplot

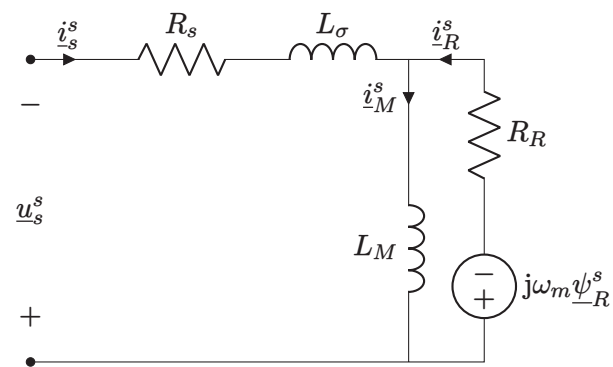


Figure 5.9: The nodes short, V, R and L are presented here, but there a lot more

5.2 Tables and figures

Table 5.1: This is a `booktabs` table

Animal	Description	Price (\$)
Gnat	per gram	13.65
	each	0.01
Gnu	stuffed	92.50
Emu	stuffed	33.33
Armadillo	frozen	8.99

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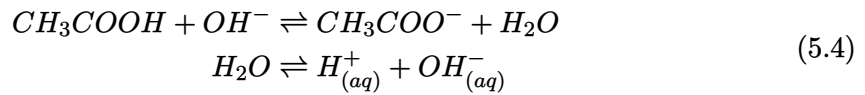
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Listing 5.1: Monte Carlo simulation to estimate the value of π

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A Bill of Materials

Table A.1: Bill of Materials for the entire system

Component	Value	Footprint	Classification	Description
Transmitter				
C1	1n	0603	X7R50V	Preamp
C13	1u	RAD-0.3in	Film 40V	Preamp
C14	1.5n	0603	X7R50V	PI controller
C15	NC	0603	X7R50V	PI controller
C2, C3, C4, C9, C10	100n	0603	X7R16V	Decoupling
C5, C11	1u	0603	X5R6.3V	Decoupling
C6, C7	100n	0805	X7R50V	Decoupling
C8	1500u	RAD-0.3in	63Vdc	Decoupling
P10	3-pin	Male	250V	Controller by-pass
P11, P12	10-pin	Female	250V	InterPCB con.
P2, P3	1-pin header	Male	250V	Measurements
P4, P5	2-way screw	NA	300V 15A	30V Power, Output
P6	2-pin header	Molex KK254	500V 4A	Audio in
P7	4-pin header	Female	250V	5V Power
P8, P9	BNC	BNC PCB	500V	Audio in, Output
R2	16.2k	0603	1%	Preamp
R1, R3	2k	0603	1%	Preamp
R4, R7	4.75k	0603	1%	Voltage ref
R5	33.2k	0603	NA	PI controller
R6	0 (short)	0603	NA	PI controller
R9	0 (short)	0603	NA	PI controller
R10	NC	0603	NA	PI controller
R8	2.49k	0603	1%	Voltage ref
U1	OPA2365	SOIC-8	NA	Preamp, PI
U2	TLV431A	SOT-23	1%	Voltage ref

Table A.1: Bill of Materials for the entire system (Continued)

Component	Value	Footprint	Classification	Description
Receiver				
C1, C11, C15, C19	100n	0603	X7R16V	Gate driver
P1, P2	10-pin header	Male	250V	InterPCB con.
C2, C16	150n	0603	X5R10V	Gate driver
C3, C10	100p	0603	NPO50V	Decoupling
L1, L2	1.768u	Radial	NA	Output filter
U1, U3	LM5113	WSO-10	NA	Gate driver
R20	15m sense	1210	1% 1W	Output filter
R1, R6	500	SMDtrim 3213	NA	Gate driver
Q1, Q2, Q3, Q4	BSZ097-N10NS5	TSDSON-8	NA	Power stage
R2, R5, R8, R10	5	0603	1%	Gate driver
R4, R9	0	0603	1%	Gate driver
D1, D2	Diode	NA	85V 0.25A	Gate driver
C5, C6, C9, C17	10u	1210	X7R50V	Decoupling
C12, C13, C14	680n	1210	X7R100V	Output filter
Microcontroller				
C18,C20,C27	100n	0603	X7R16V	Decoupling
C28, C29, C30, C31	100n	0603	X7R16V	Decoupling
U6	LT1999	MSOP-8	NA	Current acq.
U4	AD8274	MSOP-8	NA	Volt acq.
U2	LT1711	MSOP-8	NA	AIM
C4	NC	0603	X7R16V	AIM
C7	NC	0603	X7R16V	AIM
C8	NC	0603	X7R16V	Cur. acq.
CA1	1.5n	0603	X7R50V	AIM
R14	8.66k	0603	1%	AIM
R18	16.2k	0603	1%	AIM
R23	1.5k	0603	1%	AIM
R3, R11	120k	0603	1%	Voltage acq.
RA1	2.2k	0603	1%	AIM
RA2	20k	0603	1%	AIM

Continued on next page

Table A.1: Bill of Materials for the entire system (Continued)

Component	Value	Footprint	Classification	Description
RA3	2.74k	0603	1%	AIM
RA4	0	0603	NA	AIM

B Instruments

Table B.1: List of instruments used for solder work

Function	Manufacturer	Model
Visual inspection microscope	Leica	A60
Manual soldering	Weller	WX2
Heat gun	Thermaltronics	TMT-HA600-2
SMT solder paste dispensing	Fisnar	SL101N
Reflow oven	Mistral	260
DMM	Meterman	38XR

Table B.2: List of instruments used for testing

Function	Manufacturer	Model
Power supply	RIGOL	DP832A
Function generator	Keysight	33500B
DMM	Fluke	1587
Frequency response analysis	N4L	PSM1735
Audio analysis	Audio Precision	APx500
Audio analysis filter	Audio Precision	AUX-0025
Control loop analyzer	OMICRON Lab	BODE 100
Control loop injection transformer	OMICRON Lab	B-WIT 100
Passive load	Unknown	Power resistor 4 Ω
Passive load	Unknown	Loudspeaker 4 Ω
Active cooling	ebm	Test of bold