

CORDIC Background (2A)

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CORDIC Background

1.A survey of CORDIC algorithms for FPGAs, Ray Andraka,
www.andraka.com/cordic.htm

Vector Rotation (1)

$$x' = x \cos \phi - y \sin \phi$$

$$y' = y \cos \phi + x \sin \phi$$

$$x' = \cos \phi \cdot [x - y \tan \phi]$$

$$y' = \cos \phi \cdot [y + x \tan \phi]$$

$$x_{i+1} = K_i \cdot [x_i - y_i \cdot d_i \cdot 2^{-i}]$$

$$y_{i+1} = K_i \cdot [y_i + x_i \cdot d_i \cdot 2^{-i}]$$

$$K_i = \cos \phi_i = \cos(\tan^{-1}(2^{-i}))$$

$$= \frac{1}{\sqrt{1 + 2^{-2i}}}$$

$$d_i = \pm 1$$

Restrict rotation angle $\Rightarrow \tan \phi = \pm 2^{-i}$

Multiplication \Rightarrow simple shift

$$y \cdot \tan \phi$$

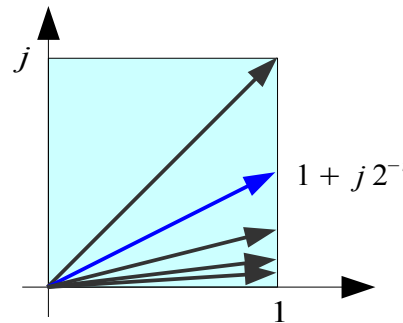
$$y \cdot 2^{-i}$$

$$x \cdot \tan \phi$$

$$x \cdot 2^{-i}$$

regardless of direction $\Rightarrow \cos(\phi) = \cos(-\phi)$

Allowed Rotation Angles



$$\tan \phi \Rightarrow 2^{-i}$$

$$\cos \phi \Rightarrow \frac{1}{\sqrt{1 + 2^{-2i}}}$$

$$K_i \leq 1$$

$$(K_i \leftarrow \cos \phi)$$

Vector Rotation (2)

$$x_{i+1} = K_i \cdot [x_i - y_i \cdot d_i \cdot 2^{-i}]$$

$$y_{i+1} = K_i \cdot [y_i + x_i \cdot d_i \cdot 2^{-i}]$$

$$K_i = \cos \phi_i = \cos(\tan^{-1}(2^{-i}))$$

$$= \frac{1}{\sqrt{1 + 2^{-2i}}} \quad K_i \leq 1$$

$$d_i = \pm 1$$

$$x_{i+1}^2 = K_i^2 \cdot [x_i^2 + y_i^2 \cdot 2^{-2i} - 2x_i y_i d_i \cdot 2^{-i}]$$

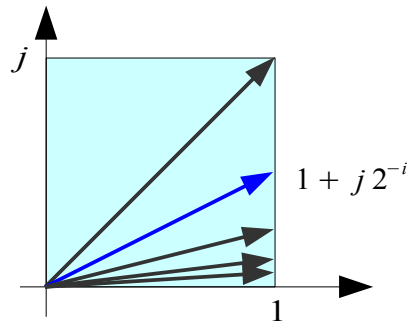
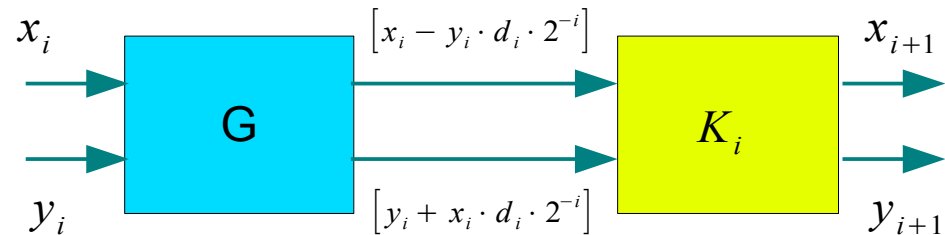
$$y_{i+1}^2 = K_i^2 \cdot [y_i^2 + x_i^2 \cdot 2^{-2i} + 2x_i y_i d_i \cdot 2^{-i}]$$

$$x_{i+1}^2 + y_{i+1}^2 = K_i^2 \cdot (1 + 2^{-2i}) \cdot (x_i^2 + y_i^2)$$

$$G \cdot K_i = 1$$

$$K_i \leq 1$$

$$G > 1$$



$$\tan \phi \rightarrow 2^{-i}$$

$$\cos \phi \rightarrow \frac{1}{\sqrt{1 + 2^{-2i}}}$$

CORDIC Gain : growing in magnitude

$$A_n = \prod_{i=1}^n \frac{1}{K_i} = \prod_{i=1}^n \sqrt{1 + 2^{-2i}} \rightarrow 1.647$$

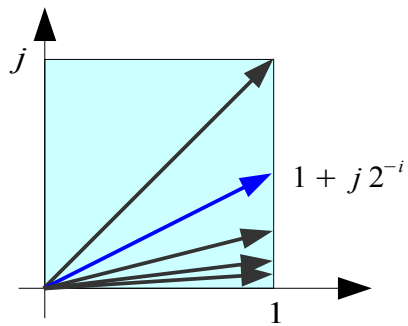
Vector Rotation (3)

$$x_{i+1} = K_i \cdot [x_i - y_i \cdot d_i \cdot 2^{-i}]$$

$$y_{i+1} = K_i \cdot [y_i + x_i \cdot d_i \cdot 2^{-i}]$$

$$K_i = 1 / \sqrt{1 + 2^{-2i}} \quad \leftarrow \cos(\phi_i)$$

$$d_i = \pm 1$$



$$\tan \phi \rightarrow 2^{-i}$$

$$\cos \phi \rightarrow \frac{1}{\sqrt{1 + 2^{-2i}}}$$

Without Scale Constants K_i

$$x_{i+1} = [x_i - y_i \cdot d_i \cdot 2^{-i}]$$

$$y_{i+1} = [y_i + x_i \cdot d_i \cdot 2^{-i}]$$

$$d_i = \pm 1$$

CORDIC Gain : *growing in magnitude*

$$A_n = \prod_{i=1}^n \frac{1}{K_i} = \prod_{i=1}^n \sqrt{1 + 2^{-2i}} \rightarrow 1.647$$

$$1 / K_i = \sqrt{1 + 2^{-2i}}$$

For correction

Multiplying K_i 's as a processing gain

$$\prod_{i=1}^n K_i = \prod_{i=1}^n \frac{1}{\sqrt{1 + 2^{-2i}}} \rightarrow 0.6073$$

Angle Accumulator

Rotation Mode

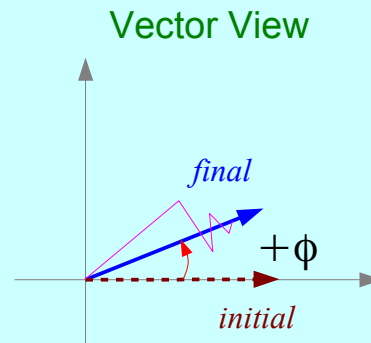
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

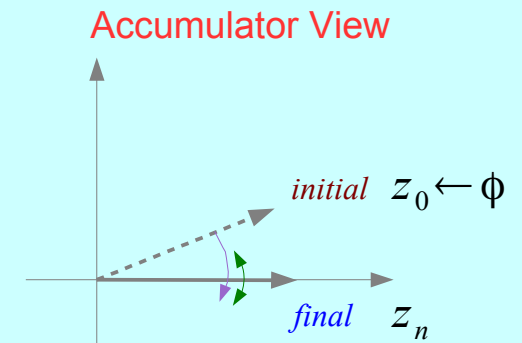
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle



Subtract angles at each step

Vectoring Mode

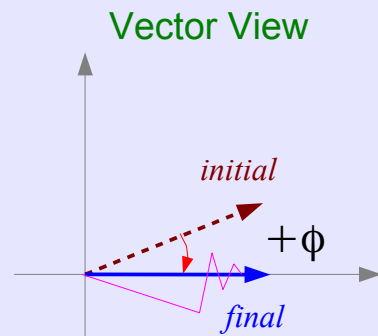
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

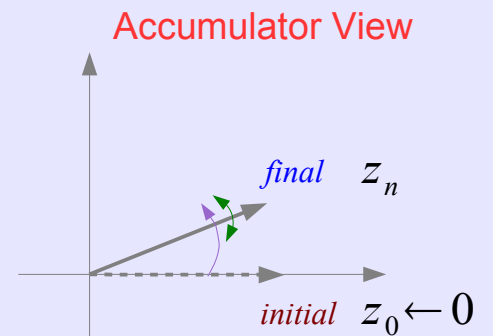
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

Angle Accumulator – Rotation Mode

Rotation Mode

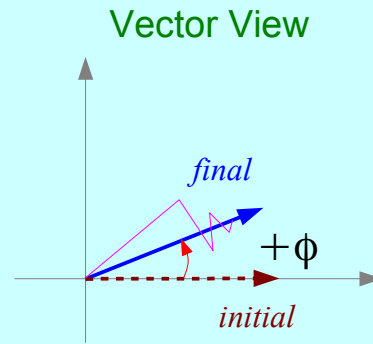
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

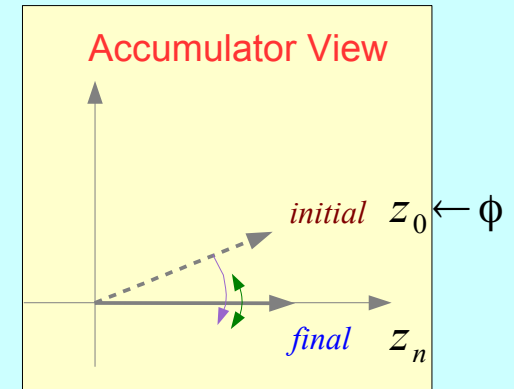
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle



Subtract angles at each step

$$z_i < 0$$

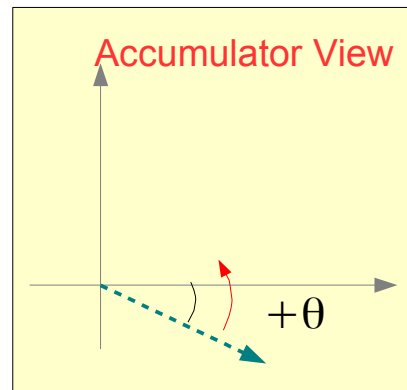
Increase Angle $d_i = -1$

$$z_{i+1} = z_i + \tan^{-1}(2^{-i})$$

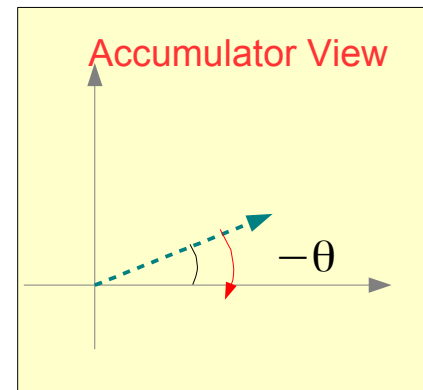
$$z_i \geq 0$$

Decrease Angle $d_i = +1$

$$z_{i+1} = z_i - \tan^{-1}(2^{-i})$$



$z_i < 0$
Increase Angle $+θ$



$z_i \geq 0$
Decreases Angle $-θ$

Angle Accumulator – Vectoring Mode

Vectoring Mode

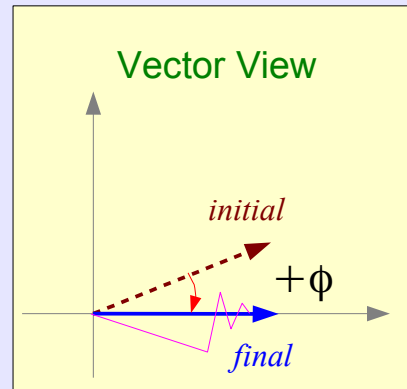
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

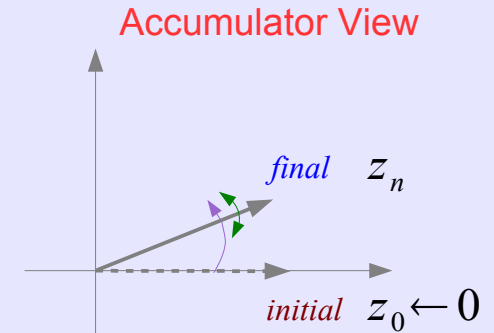
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

$$y_i < 0$$

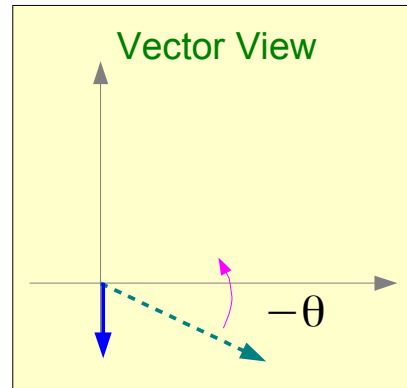
Decrease Angle $d_i = +1$

$$z_{i+1} = z_i - \tan^{-1}(2^{-i})$$

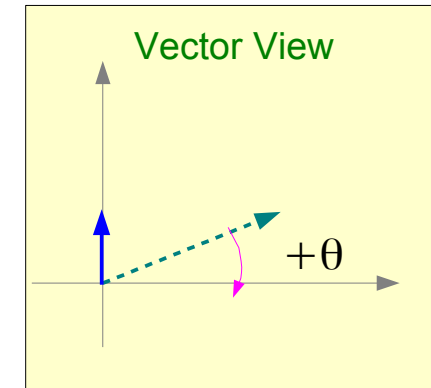
$$y_i > 0$$

Increase Angle $d_i = -1$

$$z_{i+1} = z_i + \tan^{-1}(2^{-i})$$



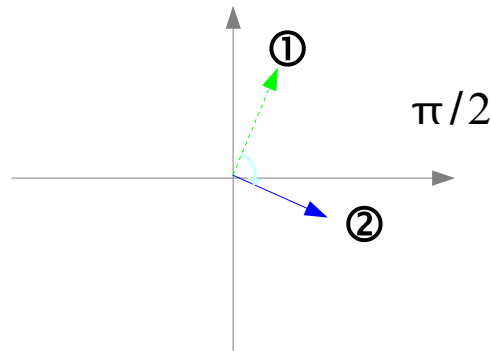
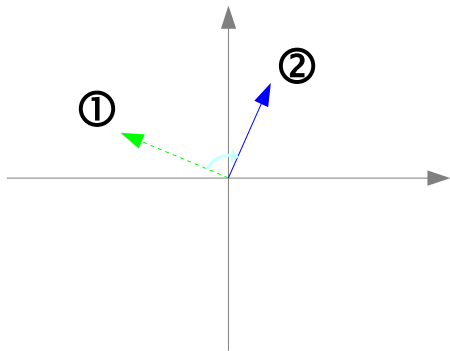
$y_i < 0$
Decrease Angle $-\theta$



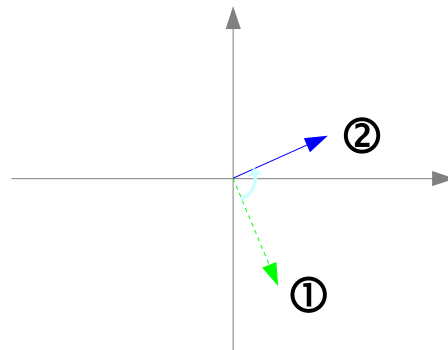
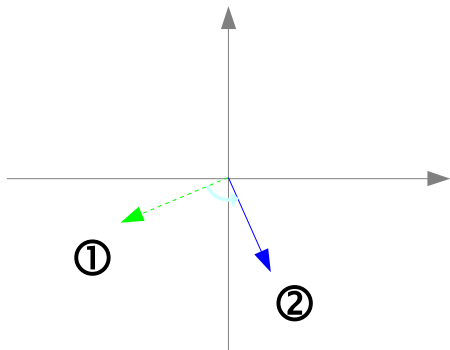
$y_i > 0$
Increases Angle $+\theta$

Initial Rotation $\pm\pi/2$

Positive Phase ($y > 0$) \rightarrow Rotate by -90 degrees



Negative Phase ($y < 0$) \rightarrow Rotate by $+90$ degrees



Resulting Phase \rightarrow $[-90, +90]$

$$\begin{aligned}x' &= -d \cdot y \\y' &= +d \cdot x \\z' &= z + d \cdot \frac{\pi}{2}\end{aligned}$$

$$d = +1 \quad \text{if } y < 0$$

$$d = -1 \quad \text{otherwise}$$

No magnitude change

$$x' \leftarrow y$$

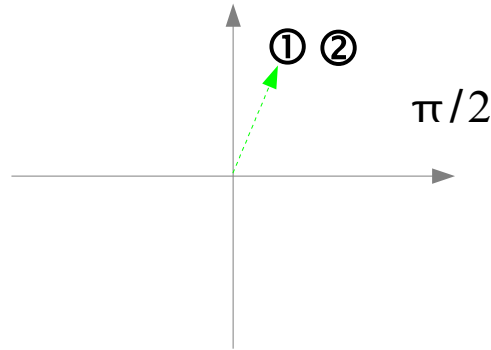
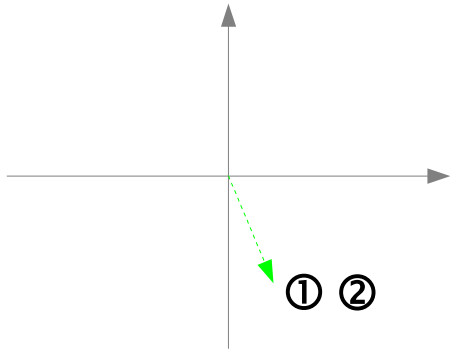
$$y' \leftarrow x$$

Consistent

Initial Rotation 0, + π

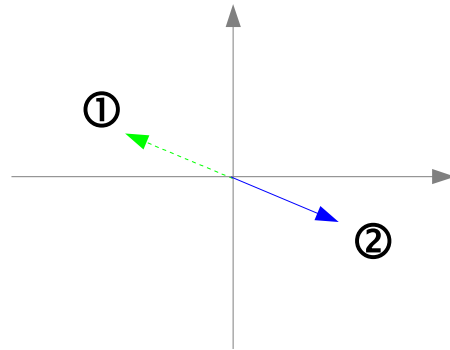
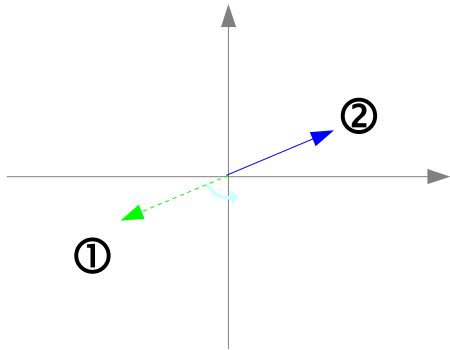
Positive x ($x > 0$)

➔ Rotate by -90 degrees



Negative x ($x < 0$)

➔ Rotate by $+90$ degrees



Resulting Phase



$[-90, +90]$

$$x' = +d \cdot x$$

$$y' = +d \cdot y$$

$$z' = z \quad \text{if } d = 1$$

$$z' = \pi - z \quad \text{if } d = -1$$

$$d = -1 \quad \text{if } x < 0$$

$$d = +1 \quad \text{otherwise}$$

No magnitude change

$$x' \leftarrow y$$

$$y' \leftarrow x$$

Convenient wiring in
FPGA

A. Sine and Cosine (1)

Rotation Mode

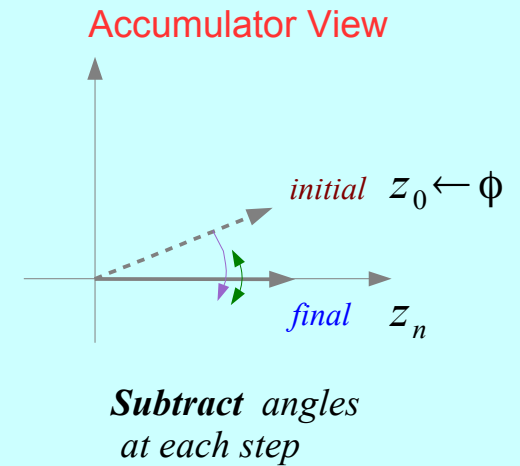
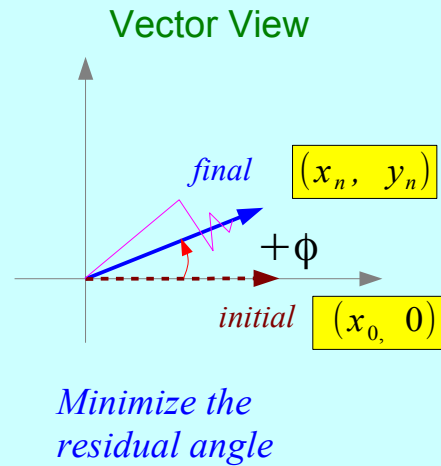
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Finding Sine and Cosine

$$(x_0, 0) \rightarrow (x_n, y_n)$$

$$x_n = A_n \cdot x_0 \cos z_0$$

$$y_n = A_n \cdot x_0 \sin z_0$$

A. Sine and Cosine (2)

Finding Sine and Cosine

$$(x_0, 0) \rightarrow (x_n, y_n)$$

$$x_n = A_n \cdot x_0 \cos z_0$$

$$y_n = A_n \cdot x_0 \sin z_0$$

Unscaled Sine and Cosine

$$\text{if } x_0 \leftarrow 1/A_n$$

$$x_n = \cos z_0$$

$$y_n = \sin z_0$$

Modulated Sine and Cosine

$$K_n \cdot x_n = K_n \cdot A_n \cdot x_0 \cos z_0$$

$$K_n \cdot y_n = K_n \cdot A_n \cdot x_0 \sin z_0$$

$$K_n \cdot x_n = x_0 \cos z_0$$

$$K_n \cdot y_n = x_0 \sin z_0$$

Look Up Table

→ a pair of MULT

CORDIC method

→ MULT as a part of rotation

B. Polar to Rectangular

Rotation Mode

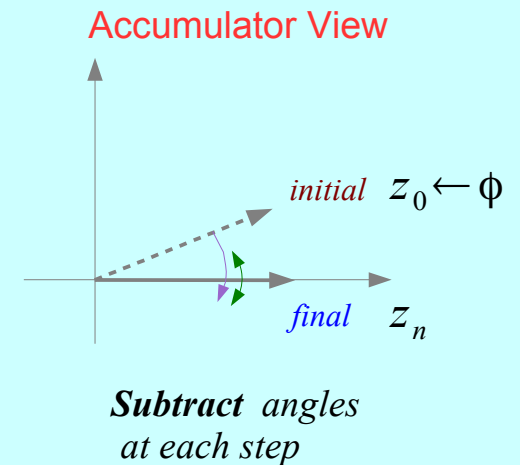
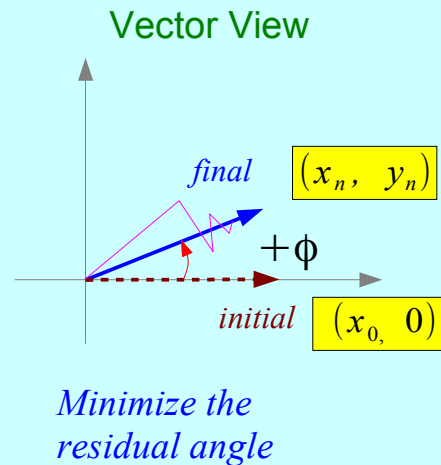
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Finding Sine and Cosine

$$(x_0, 0) \rightarrow (x_n, y_n)$$

$$x_n = A_n \cdot x_0 \cos z_0$$

$$y_n = A_n \cdot x_0 \sin z_0$$

$$x_0 \leftarrow r$$

$$x_n \rightarrow r \cos \theta$$

$$z_0 \leftarrow \theta$$

$$y_n \rightarrow r \sin \theta$$

B. Polar to Rectangular

Rotation Mode

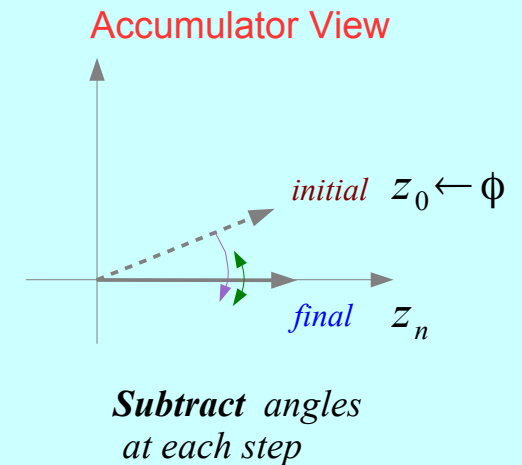
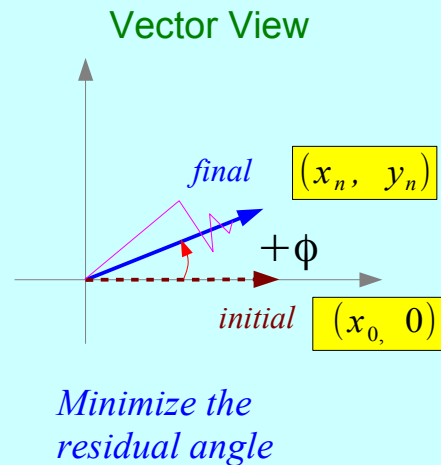
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Finding Sine and Cosine

$$(x_0, 0) \rightarrow (x_n, y_n)$$

$$x_n = A_n \cdot x_0 \cos z_0$$

$$y_n = A_n \cdot x_0 \sin z_0$$

$$x_0 \leftarrow r$$

$$x_n \rightarrow r \cos \theta$$

$$z_0 \leftarrow \theta$$

$$y_n \rightarrow r \sin \theta$$

C. General Vector Rotation

Rotation Mode

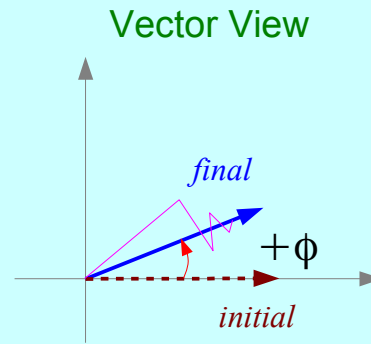
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

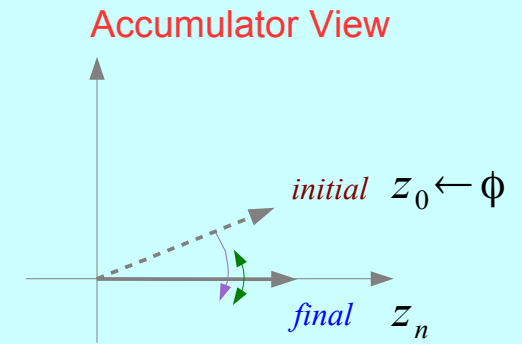
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle

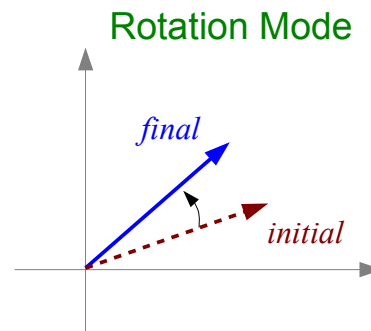


Subtract angles at each step

Motion Correction and Control System

$$x_n = A_n [x_0 \cdot \cos z_0 - y_0 \cdot \sin z_0]$$

$$y_n = A_n [x_0 \cdot \sin z_0 + y_0 \cdot \cos z_0]$$



C.

Vectoring Mode

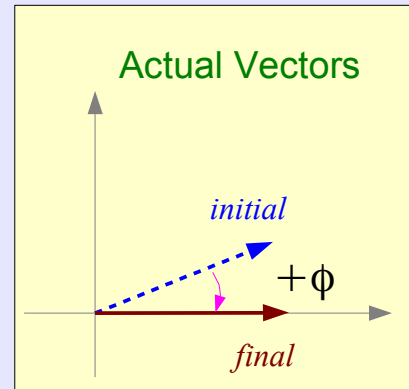
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

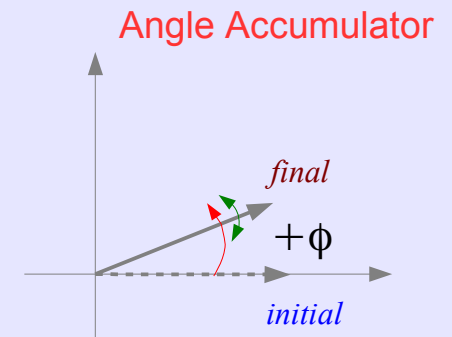
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



*Add angles
at each step*



*Minimize the
residual y comp.*

References

- [1] <http://en.wikipedia.org/>
- [2] CORDIC FAQ, www.dspguru.com