2-D Mapping with Sonar

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Basic Sonar





- Ultrasound cannot be heard by people
- Small wavelength => good for short
- Time of flight can be used to estimate





Basic Mapping



 Rotate receiver/ transmitter to measure distance at every angle

 Slow update rates because of many distance measurements

Phase Array







 Use multiple receivers, measure different angles using phase relationships

- No moving parts => more reliable
- Faster update rate

Applications





 Draw a top view map of environment

 Security system that detects changes in surroundings



Simplified Block Diagram



Datagathering Process Interface

Transmit/Receive





Transmit/Receive



Transmit a single
 40-kHz sine wave
 pulse (generated
 from stored values
 played through DAC)

Multiple receivers

 Enable signals from Control Module for transmitting and receiving





Data-gathering







Data-gathering



 Samples data from receivers at intervals dictated by Control Module

 Data stored in one of two RAMs

 Simultaneous storage and processing of data— "double buffering"





Control/Process



Transmit/ Data-Receive gathering





 Control Module gives Processing Module an angle;
 Processing Module gives back distance at that angle

Display/

Interface

 Post-Processor gets angle/distance pairs ready for display and tells Control Module if more data is needed

Transmit/Data-
gatheringControl/
Process

Display/Interface



Display/Interface





- Display Module gives VGA controller appropriate RGB signals
- Main purpose is to draw a 2-D, colorcoded map of the environment
- RS232 Module is for debugging
- User can choose what is displayed



Sines, Chirps, and Pulses



What kind of signal to transmit?

Steady Sine Wave

 Chirp (linearly changing frequency)

 Short pulsed sine wave



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Game Plan







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 For each reflection, different receivers have similar attenuation, but slight phase shifts.

Can expand as 2 delays:

Object to receiver1 - DISTANCE

Receiver 1 to
 Receiver N DIRECTION



The Process



 Find where a certain phase relation is most likely to have occurred (similar to matched filtering)

- 2. Record the delay to this region of the signal
- 3. Distance = (half
 delay to max) *
 (speed of sound)



The Process



After post-processing, matches almost perfectly in simulation.