Hybrid CORDIC 1.A Sine/Cosine Generator Algorithms

20171206

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The details moved to

https://en.wikiversity.org/wiki/Butterfly_Hardware_Implementations

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Wilson ROM based Sine/Cosine Generation

[24] Fu & Willson Sine / Cosine Generation

ROM-based approach

For high resolution, ROM size grows exponentially

quater-wave symmetry

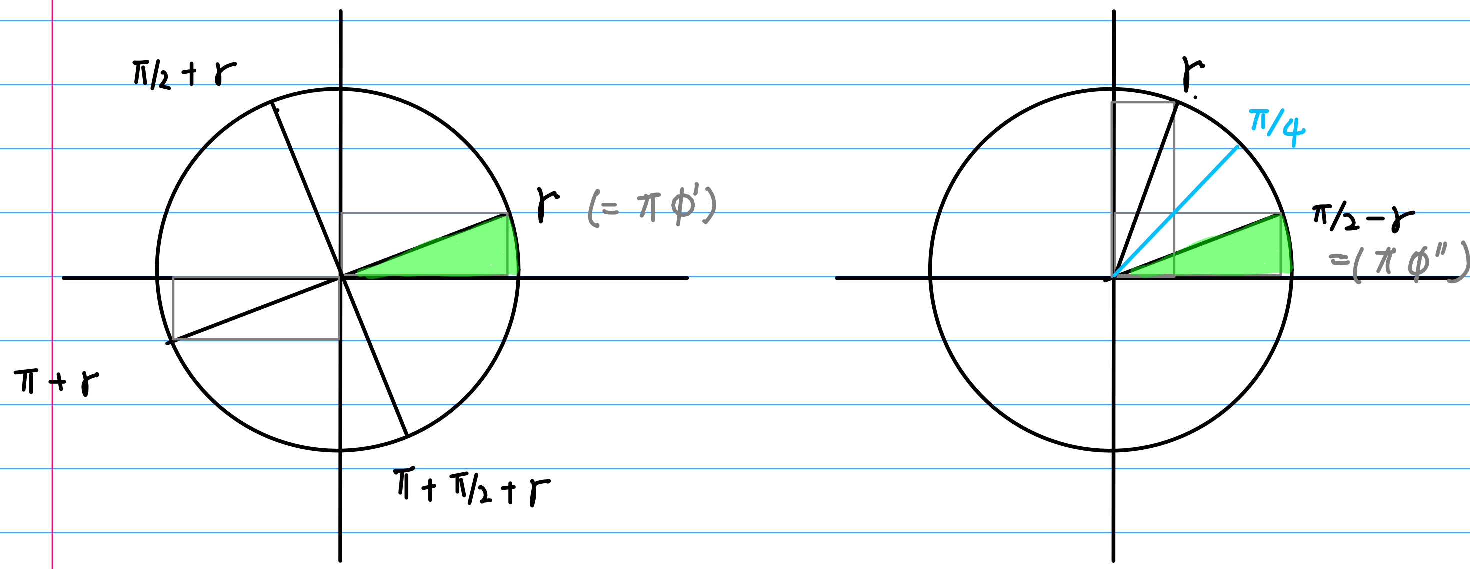
$$\sin\theta = \cos\left(\frac{\pi}{2} - \theta\right)$$

$$\phi \ [0, 2\pi] \longrightarrow [0, \tfrac{\pi}{4}]$$

conditionally interchanging inputs X_0 & Y_0
Conditionally interchanging and negating outputs X & Y

$$X = X_0 \cos\phi - Y_0 \sin\phi$$
$$Y = Y_0 \cos\phi + X_0 \sin\phi$$

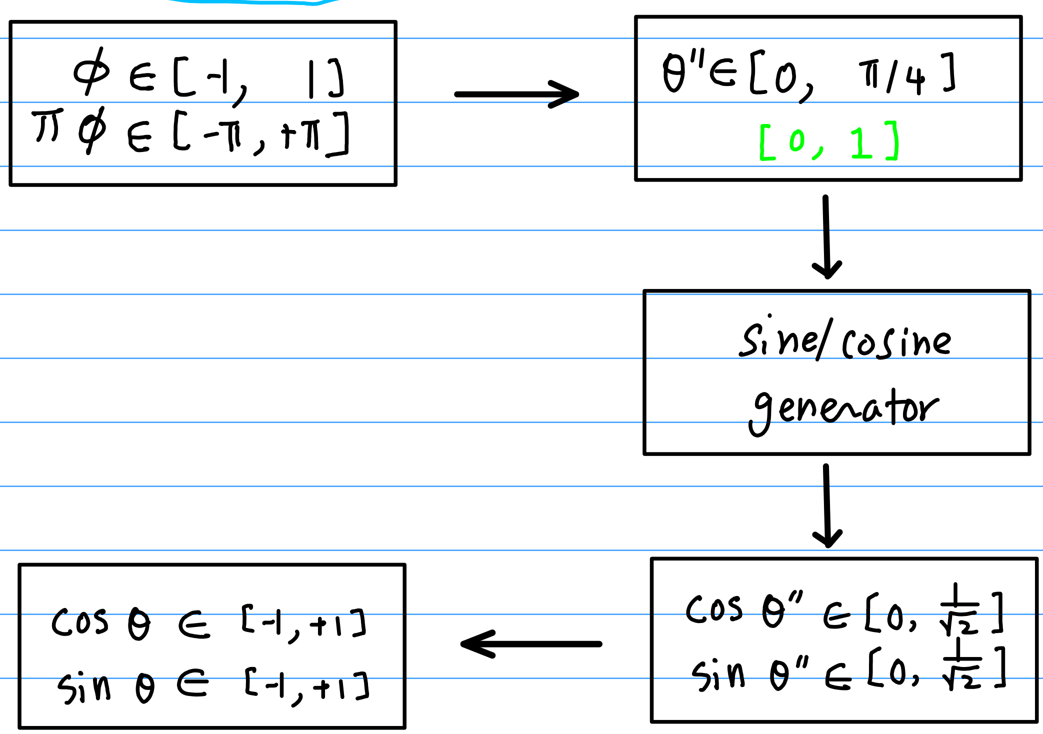
Madisetti VLSI arch



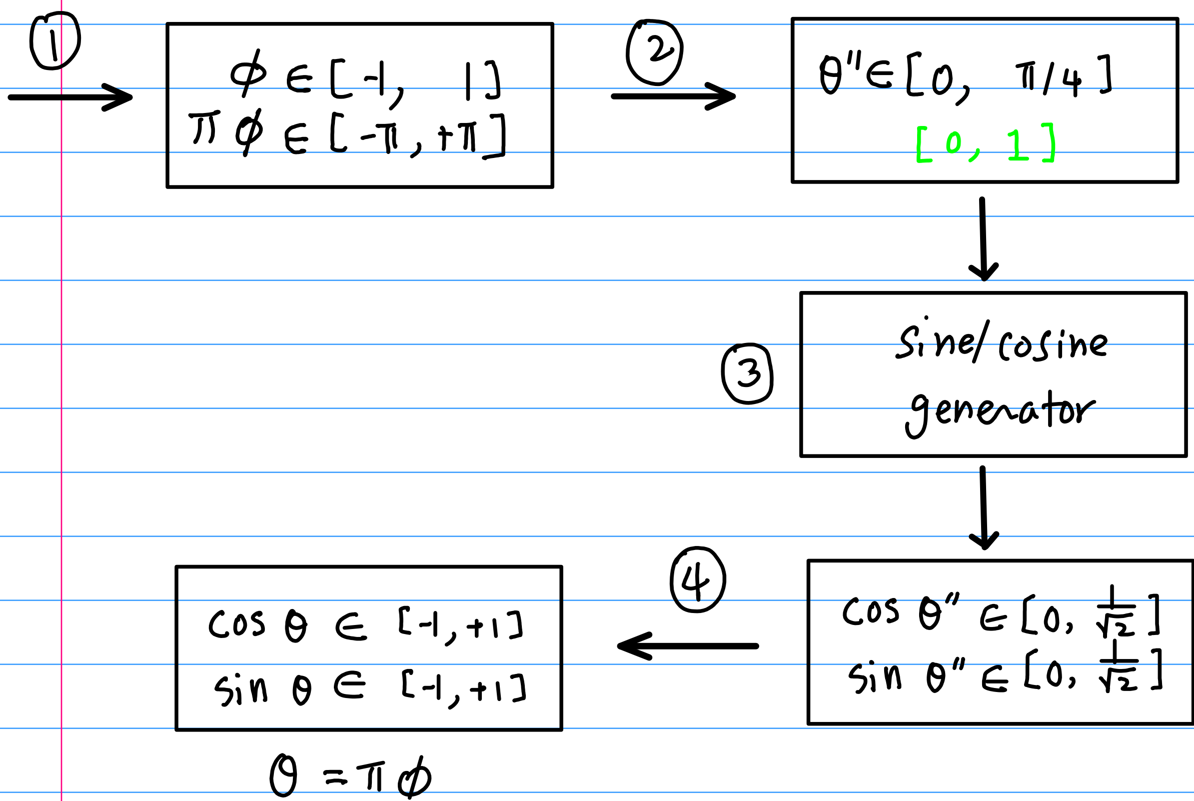
frequency Synthesis

argument : signed angle $\phi \in [-1, 1]$ normalized by π

unsigned radian angle (fraction) in binary representation



$\theta = \pi \phi$

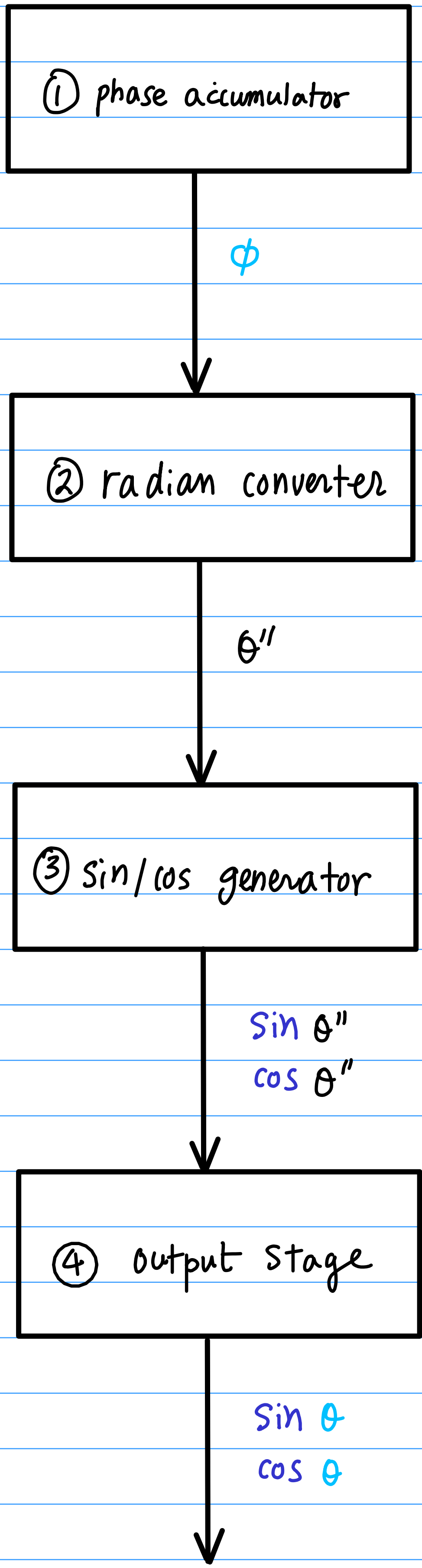


① a phase accumulator $\phi \in [-1, 1]$

② a radian converter $\theta'' \in [0, 1]$

③ a sine/cosine generator $\sin\theta''$, $\cos\theta''$

④ an output stage $\sin\theta$, $\cos\theta$



$\phi \in [-1, +1]$

normalized by π

angles must be in <u>radian</u>

for angle rotations

$MSB_1(\phi)$ $MSB_2(\phi)$ Quadrant

$MSB_3(\phi)$ $< \frac{\pi}{4}$

$-\pi < \theta = \pi\phi < \pi$

$0 < \theta'' = \pi\phi'' < \frac{\pi}{4}$

N-bit binary representation of θ''

the direction of subangle rotation

$b_k \in \{0, 1\} \longrightarrow r_k \in \{-1, +1\}$

angle recoding

$0 < \theta'' = \pi\phi'' < \frac{\pi}{4}$

$-\pi < \theta = \pi\phi < +\pi$

Radian Converter

$$0 < \theta'' = \pi \phi'' < \frac{\pi}{4}$$

normalized angle ϕ

ϕ	MSB1	MSB2	MSB3				...		

1st Quadrant

ϕ'	0	0	MSB3				...		

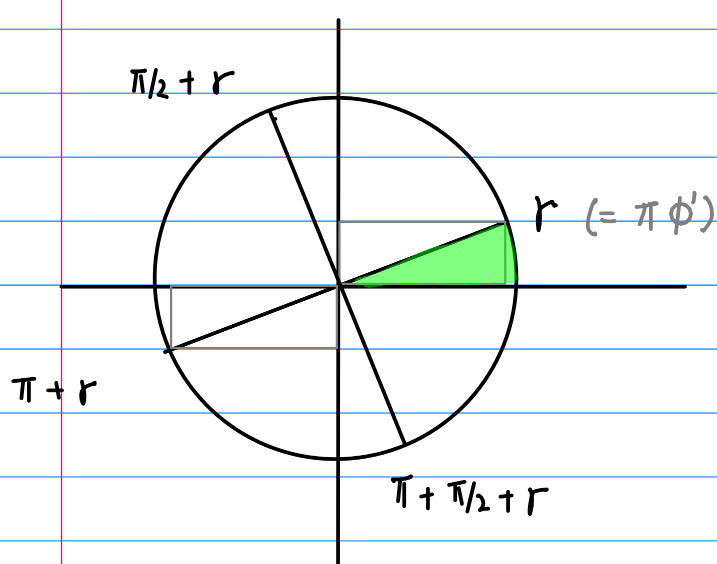
MSB3 = 0 $\quad \phi'' = \phi'$

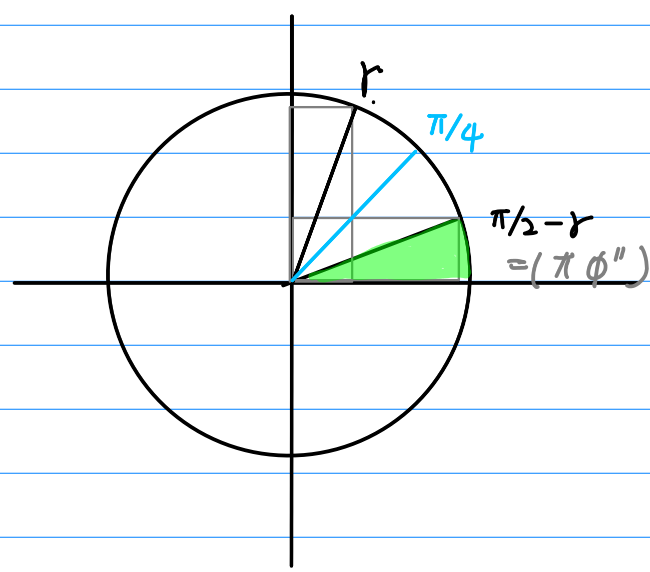
MSB3 = 1 $\quad \phi'' = 0.5 - \phi'$

$0.5 - \phi'$	0	1	0	$\bar{a}_4$	$\bar{a}_5$	$\bar{a}_6$	...		$\bar{a}_N$

+1

MSB1, MSB2, MSB3 → xinv | yinv | swap





Angle Recoding

$\boxed{MSB_1}\boxed{MSB_2}\boxed{MSB_3} \longrightarrow 0 < \theta'' < 1 \longrightarrow$ recoding $\{r_k\}$

$$\sum_{k=1}^{N} b_k \cdot 2^{-k} = \phi_0 + \sum_{k=2}^{N+1} r_k \cdot 2^{-k}$$

$b_k \in \{0, 1\}$ $\qquad$ $r_k \in \{-1, +1\}$

$$\begin{cases} b_k = 1 \longrightarrow r_{k+1} = +1 \\ b_k = 0 \longrightarrow r_{k+1} = -1 \end{cases}$$

$$r_k = (2b_{k-1} - 1)$$

ϕ_0 depends only on bit width N

for fixed N, $\phi_0 = \frac{1}{2} - \frac{1}{2^{N+1}}$ is a constant

Sine / Cosine Generator Overview

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix} \Rightarrow \begin{bmatrix} \cos\theta \\ \sin\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

a sequence of subrotations of the priori known angle

$$\theta = \sigma_0\theta_0 + \sigma_1\theta_1 + \cdots + \sigma_N\theta_N$$

$$\sigma_k = \{-1, 0, +1\}$$

① $\theta_k = \tan^{-1} 2^{-k}$ traditional CORDIC

② $\theta_k = 2^{-k}$ possible because $\theta'' < 1$

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$= K \begin{bmatrix} 1 & -\tan(\sigma_0\theta_0) \\ \tan(\sigma_0\theta_0) & 1 \end{bmatrix} \begin{bmatrix} 1 & -\tan(\sigma_1\theta_1) \\ \tan(\sigma_1\theta_1) & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\tan(\sigma_N\theta_N) \\ \tan(\sigma_N\theta_N) & 1 \end{bmatrix}$$

$K = \cos(\sigma_0\theta_0)\cos(\sigma_1\theta_1)\cdots\cos(\sigma_N\theta_N)$ scale factor

$\sigma_k = +1$ positive angle rotation

$\sigma_k = -1$ negative angle rotation

The scaling K.

The initial rotation $\phi_0 = \frac{1}{2} - \frac{1}{2^{N+1}}$

rotation starting point

$$(X_0, Y_0) = (K\cos\phi_0,\ K\sin\phi_0)$$

rotation always starts from this fixed point.

cascade of feed forward rotational stages

$$\theta \rightarrow \boxed{MSB_1}\boxed{MSB_2}\boxed{MSB_3} \rightarrow \theta'' \rightarrow b_k 2^{-k} \rightarrow r_k 2^{-k}$$

binary representation — recoding

{ no comparison
  no error build up

① $\theta_k = \tan^{-1} 2^{-k}$ — traditional CORDIC

☆ ② $\theta_k = 2^{-k}$ — possible because $\theta'' < 1$

$$\begin{bmatrix} 1 & -\sigma_k \tan(2^{-k}) \\ \sigma_k \tan(2^{-k}) & 1 \end{bmatrix}$$

Subrotation angle θ_k

① $\theta_k = \tan^{-1} 2^{-k}$ traditional CORDIC

$$\begin{bmatrix} 1 & -\sigma_k \tan(\tan^{-1} 2^{-k}) \\ \sigma_k \tan(\tan^{-1} 2^{-k}) & 1 \end{bmatrix} \Rightarrow \begin{bmatrix} 1 & -\sigma_k 2^{-k} \\ \sigma_k 2^{-k} & 1 \end{bmatrix}$$

☆ ② $\theta_k = 2^{-k}$ possible because $\theta'' < 1$

$$\begin{bmatrix} 1 & -\sigma_k \tan(2^{-k}) \\ \sigma_k \tan(2^{-k}) & 1 \end{bmatrix} \Rightarrow \left\{ \begin{array}{l} \begin{bmatrix} 1 & -\sigma_k \tan(2^{-k}) \\ \sigma_k \tan(2^{-k}) & 1 \end{bmatrix} \\ \\ \begin{bmatrix} 1 & -\sigma_k 2^{-k} \\ \sigma_k 2^{-k} & 1 \end{bmatrix} \end{array} \right.$$

$\tan(2^{-k}) \cong 2^{-k}$ $k \geq k_0$

the $\tan \theta_k$ multipliers used in the first few subrotation stages cannot be implemented as simple shift-and-add operations

① Subrotation angle $\theta_k = \tan^{-1} 2^{-k}$ traditional

$$K = \cos(\theta_0)\cos(\theta_1)\cdots\cos(\theta_N)$$

$$K \begin{bmatrix} 1 & -\tan(\sigma_0\theta_0) \\ \tan(\sigma_0\theta_0) & 1 \end{bmatrix} \begin{bmatrix} 1 & -\tan(\sigma_1\theta_1) \\ \tan(\sigma_1\theta_1) & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\tan(\sigma_N\theta_N) \\ \tan(\sigma_N\theta_N) & 1 \end{bmatrix}$$

$\theta_k = \tan^{-1} 2^{-k}$ → $\tan \theta_k = 2^{-k}$

$$K \begin{bmatrix} 1 & -\sigma_0 2^{-0} \\ \sigma_0 2^{-0} & 1 \end{bmatrix} \begin{bmatrix} 1 & -\sigma_1 2^{-1} \\ \sigma_1 2^{-1} & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\sigma_N 2^{-N} \\ \sigma_N 2^{-N} & 1 \end{bmatrix}$$

↳ shift-and-add

② Subrotation angle $\theta_k = 2^{-k}$ recoding

$$K = \cos(\theta_0)\cos(\theta_1)\cdots\cos(\theta_N)$$

$$K\begin{bmatrix}1 & -\tan(\sigma_0\theta_0)\\ \tan(\sigma_0\theta_0) & 1\end{bmatrix}\begin{bmatrix}1 & -\tan(\sigma_1\theta_1)\\ \tan(\sigma_1\theta_1) & 1\end{bmatrix}\cdots\begin{bmatrix}1 & -\tan(\sigma_N\theta_N)\\ \tan(\sigma_N\theta_N) & 1\end{bmatrix}$$

☆ $\theta_k = 2^{-k}$ → $\tan\theta_k = \tan 2^{-k}$

$$K\begin{bmatrix}1 & -\sigma_0\tan(2^{-0})\\ \sigma_0\tan(2^{-0}) & 1\end{bmatrix}\begin{bmatrix}1 & -\sigma_1\tan(2^{-1})\\ \sigma_1\tan(2^{-1}) & 1\end{bmatrix}\cdots\begin{bmatrix}1 & -\sigma_N\tan(2^{-N})\\ \sigma_N\tan(2^{-N}) & 1\end{bmatrix}$$

$\tan(2^{-k}) \cong 2^{-k}$ $\quad k \geq k_0$

$$K\begin{bmatrix}1 & -\sigma_0\tan(2^{-0})\\ \sigma_0\tan(2^{-0}) & 1\end{bmatrix}\cdots\begin{bmatrix}1 & -\sigma_{k_0}2^{-k_0}\\ \sigma_{k_0}2^{-k_0} & 1\end{bmatrix}\cdots\begin{bmatrix}1 & -\sigma_N 2^{-N}\\ \sigma_N 2^{-N} & 1\end{bmatrix}$$

← → ← simple shift-and-add →

ROM implementation	shift-and-add

reduced chip area

higher operating speed.

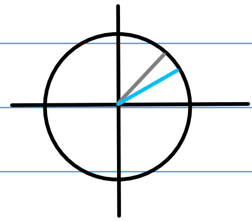
the desired output **precision in bits** determines the **number of Stages**

- the rotations always start from the fixed point
- a cascade of **feed forward** rotational Stages

the algorithm does not suffer from an **error build up** which limits the accuracy of most **recursive** digital oscillator structures

Architecture

1. phase accumulator $\phi \in [-1, +1]$
2. radian converter $\theta'' \in [0, \frac{\pi}{4}]$
3. Sine/cosine generator $\sin(\theta'')$ $\cos(\theta'')$
4. Output stage $\sin(\pi\phi)$ $\cos(\pi\phi)$



1st half quadrant

$\phi \in [-1, +1]$ normalized angle

$\pi\phi \in [-\pi, +\pi] \rightarrow \theta \in [0, \frac{\pi}{4}]$

$\sin(\theta'')$ $\cos(\theta'')$

$\sin(\pi\phi)$ $\cos(\pi\phi)$

Overflowing 2's complement accumulator

normalized by π angle ϕ

need radian angle $\theta \in [0, \frac{\pi}{4}]$

$0 < \theta < 1$ rad

N-bit binary representation of θ

controls the direction of subrotation

N-bit precision of $\cos\theta$ & $\sin\theta$

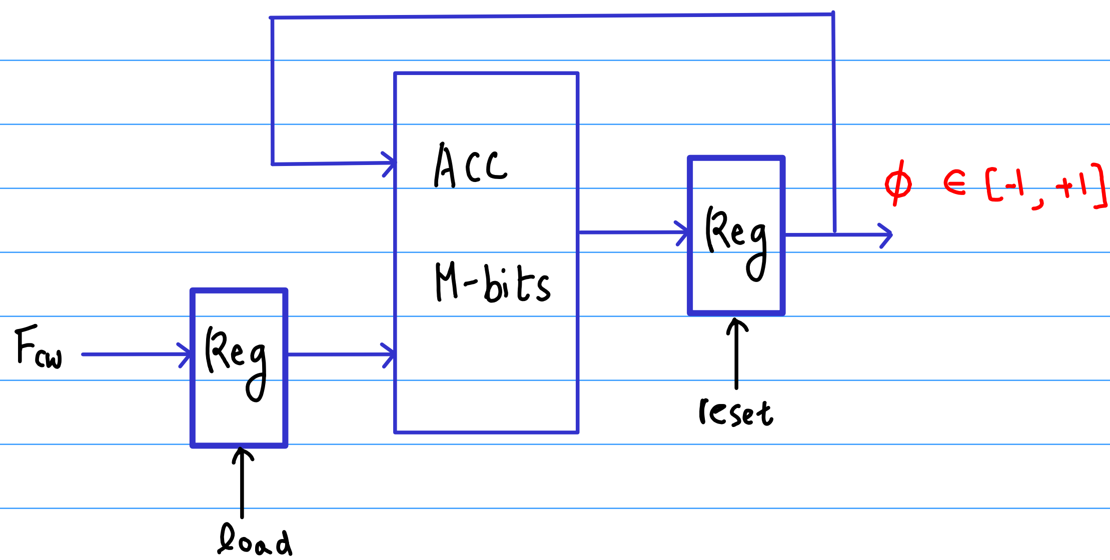
Output stage

$\theta \rightarrow \pi\phi$

$\sin\theta \rightarrow \sin\pi\phi$

$\cos\theta \rightarrow \cos\pi\phi$

① phase accumulator



M-bit adder — repeatedly increments the phase a

by F_{cw} at each clock cycle

frequency control word

at time n, $\boxed{\phi = n F_{cw}/2^M}$

$$\cos\phi = \cos(n F_{cw}/2^M)$$
$$\sin\phi = \sin(n F_{cw}/2^M)$$

$$-1 < \phi < +1$$

normalized angle

Normalized Angle

at time n,

$$\phi = n F_{cw} / 2^{M}$$

$$\cos\phi = \cos(n F_{cw} / 2^{M})$$
$$\sin\phi = \sin(n F_{cw} / 2^{M})$$

$-1 < \phi < +1$ ϕ radians$/\pi$

$-\pi < \pi\phi < +\pi$ $\pi\phi$ radians

$-\pi < \theta < +\pi$ θ radians

$$\theta = \pi\phi$$

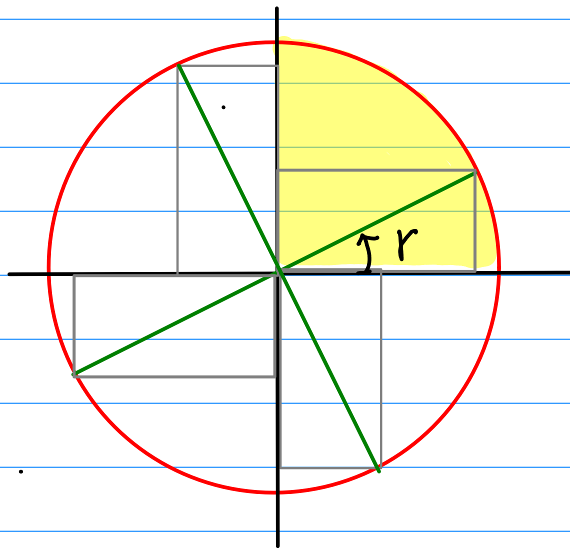
$$\theta \in [-\pi, +\pi]$$
$$\phi \in [-1, +1]$$

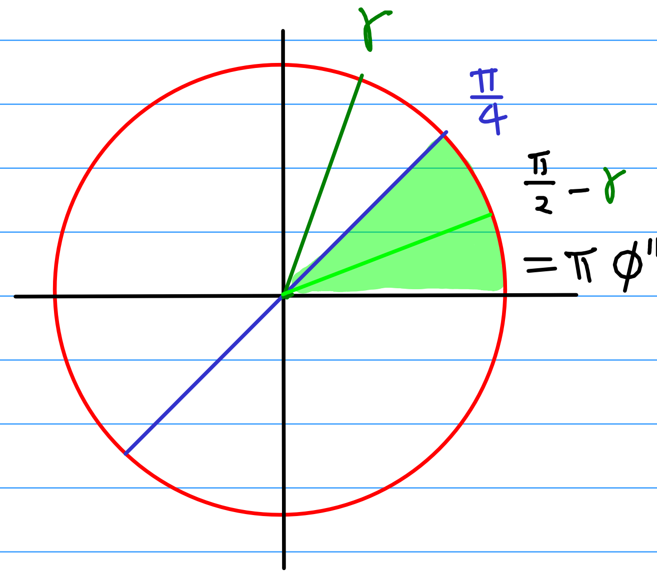
② Radian Converter

$\theta = \pi\phi \rightarrow \theta' = \pi\phi' \rightarrow \theta'' = \pi\phi''$

$\theta \in [-\pi, +\pi] \rightarrow \theta' = [0, \pi/2] \rightarrow \theta'' = [0, \pi/4]$

$\phi \in [-1, +1] \rightarrow \phi' = [0, 0.5] \rightarrow \phi'' = [0, 0.25]$





$\theta' = \pi\phi'$ $\theta'' = \pi\phi''$

$-1 < \phi < +1$
$-\pi < \pi\phi < +\pi$
$-\pi < \theta < +\pi$

radian

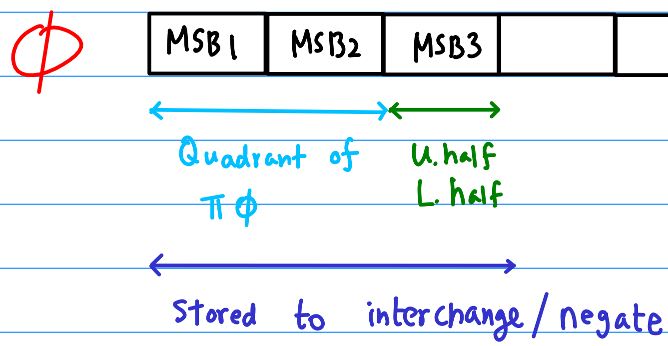
MSB_1
MSB_2
MSB_3

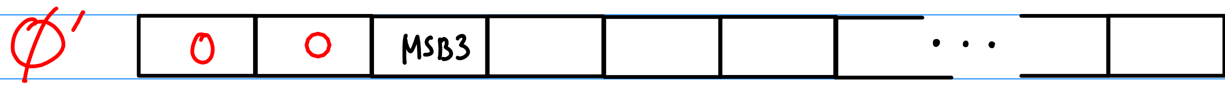
↔

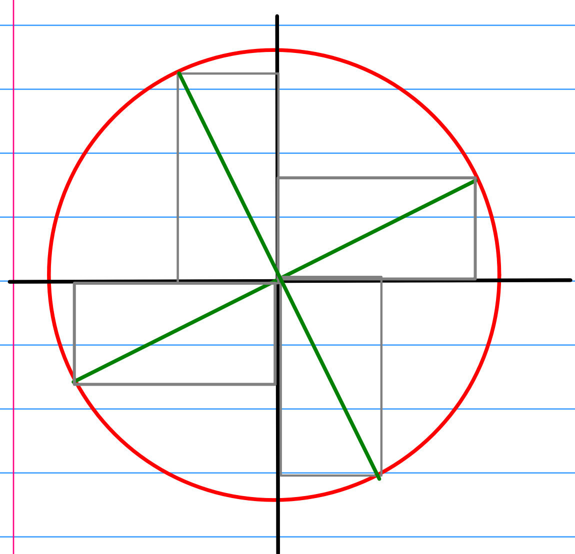
$0 < \phi'' < 1/4$
$0 < \pi\phi'' < \pi/4$
$0 < \theta'' < 1$

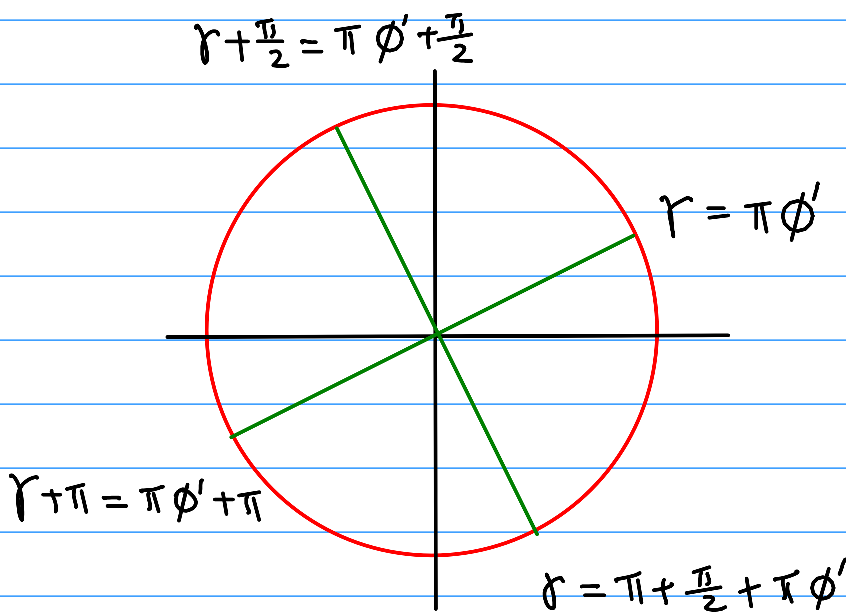
radian

normalized angle ϕ







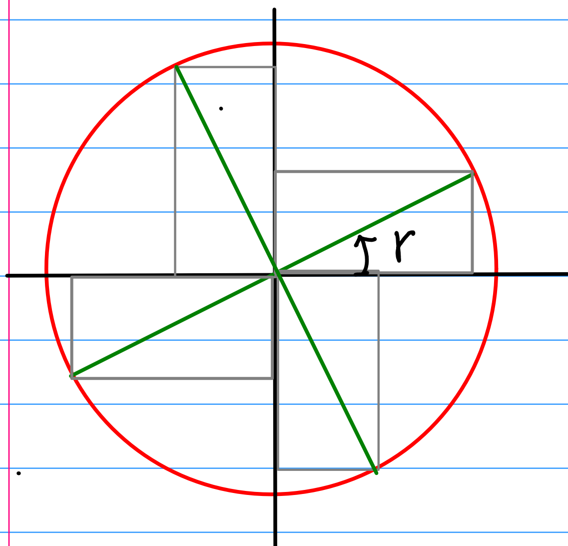


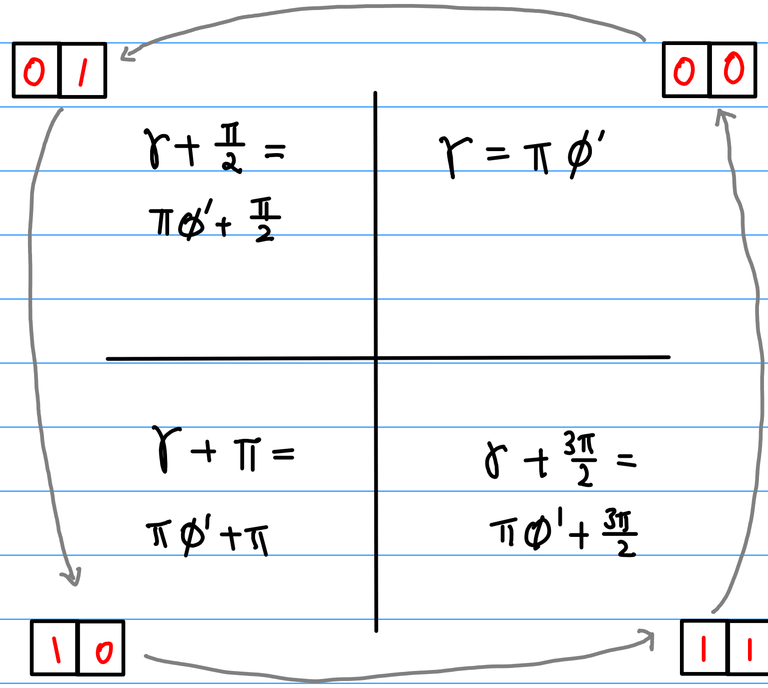
$\phi \rightarrow \phi' \rightarrow$

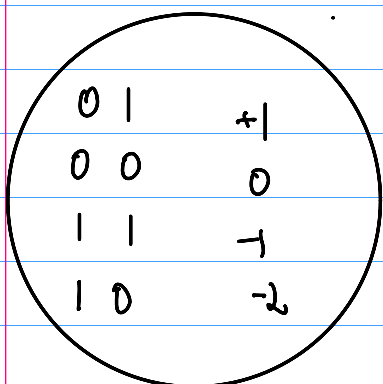
↑ 1st Quad

$\pi\phi'$	$+\ 0 \cdot \frac{\pi}{2}$	00
$\pi\phi'$	$+\ 1 \cdot \frac{\pi}{2}$	01
$\pi\phi'$	$+\ 2 \cdot \frac{\pi}{2}$	10
$\pi\phi'$	$+\ 3 \cdot \frac{\pi}{2}$	11

Quadrant Symmetry







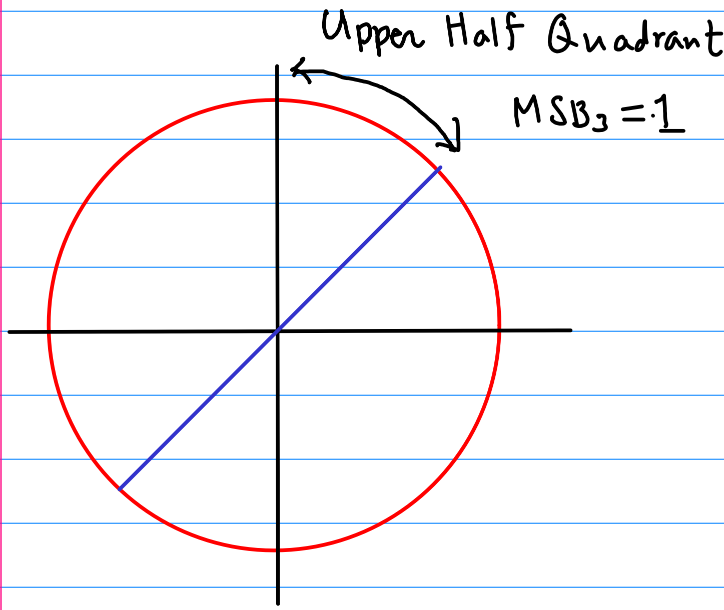
$$\theta = \pi\phi \rightarrow \theta' = \pi\phi'$$

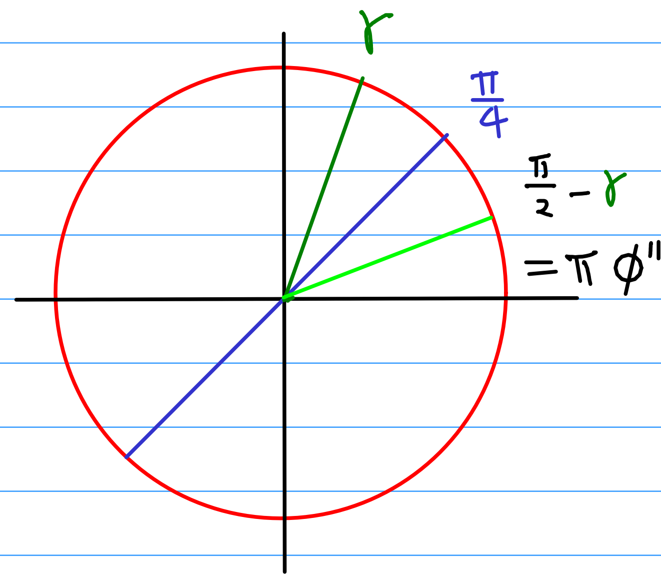
$$\theta \in [-\pi, +\pi] \rightarrow \theta = [0, \frac{\pi}{2}]$$

$$\phi \in [-1, +1] \rightarrow \phi' = [0, 0.5]$$

ϕ'

1st Quadrant



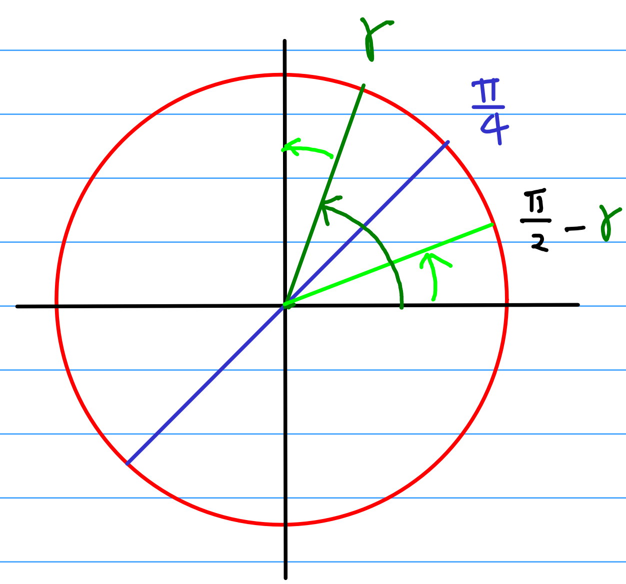


$\gamma > \frac{\pi}{4}$: Upper Half ($MSB_3 = 1$)

$\gamma < \frac{\pi}{4}$: Lower Half ($MSB_3 = 0$)

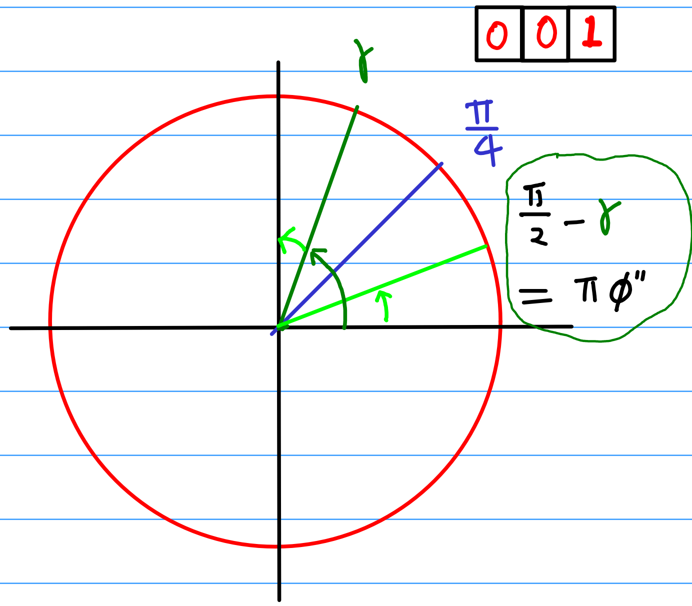
$$\cos\gamma = \sin\left(\frac{\pi}{2} - \gamma\right)$$

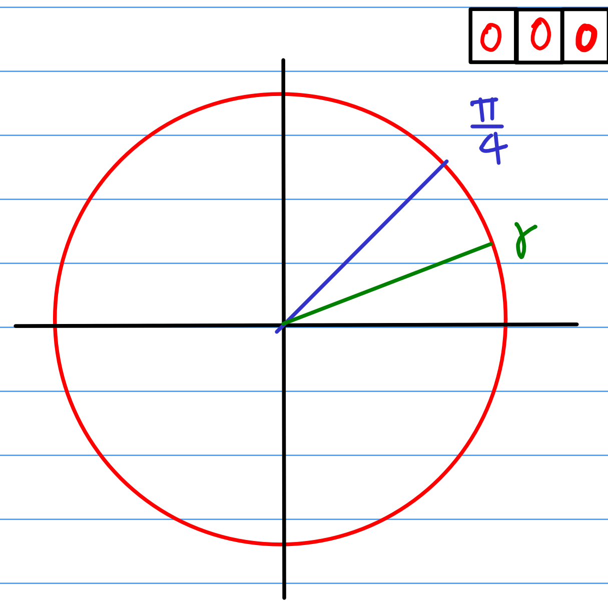
$$\sin\gamma = \cos\left(\frac{\pi}{2} - \gamma\right)$$



$\gamma > \frac{\pi}{4}$ $\quad \frac{\pi}{2} - \gamma < \frac{\pi}{4}$.

π/4 mirror





$\frac{\pi}{4} < \gamma < \frac{\pi}{2}$

$\phi'' = 0.5 - \phi'$

$0 < \gamma < \frac{\pi}{4}$

$\phi'' = \phi'$

$\theta = \pi \phi \rightarrow \theta' = \pi \phi' \rightarrow \theta'' = \pi \phi''$

$\theta \in [-\pi, +\pi] \rightarrow \theta' = [0, \pi/2] \rightarrow \theta'' = [0, \pi/4]$

$\phi \in [-1, +1] \rightarrow \phi' = [0, 0.5] \rightarrow \phi'' = [0, 0.25]$

ϕ'	0	0	MSB3					…	

$MSB3 = 1 \qquad \phi' > \frac{\pi}{4}$

$$\phi'' = \frac{\pi}{2} - \phi'$$

0.5	1	0	0					…	
$\ominus$ ϕ'	0	0	MSB3					…	

$$\begin{cases} MSB3 = 0 & \phi'' = \phi' \\ MSB_3 = 1 & \phi'' = 0.5 - \phi' \end{cases}$$

$\theta = \pi \phi''$ (Handwired Multiplier)

$0 < \theta < \frac{\pi}{4}$

$\phi \longrightarrow \phi' \longrightarrow \phi''$

1st Quad   Lower Half

$$\phi \longrightarrow \phi' \longrightarrow \phi''$$

normalized angle ϕ

ϕ	MSB1	MSB2	MSB3				...		

1st Quadrant

ϕ'	0	0	MSB3				...		

MSB3	= 0	$\phi'' = \phi'$
MSB3	= 1	$\phi'' = 0.5 - \phi'$

0.5	1	0	0	0	0	0	...	0
$- \phi'$	0	0	1	a_4	a_5	a_6	...	a_N

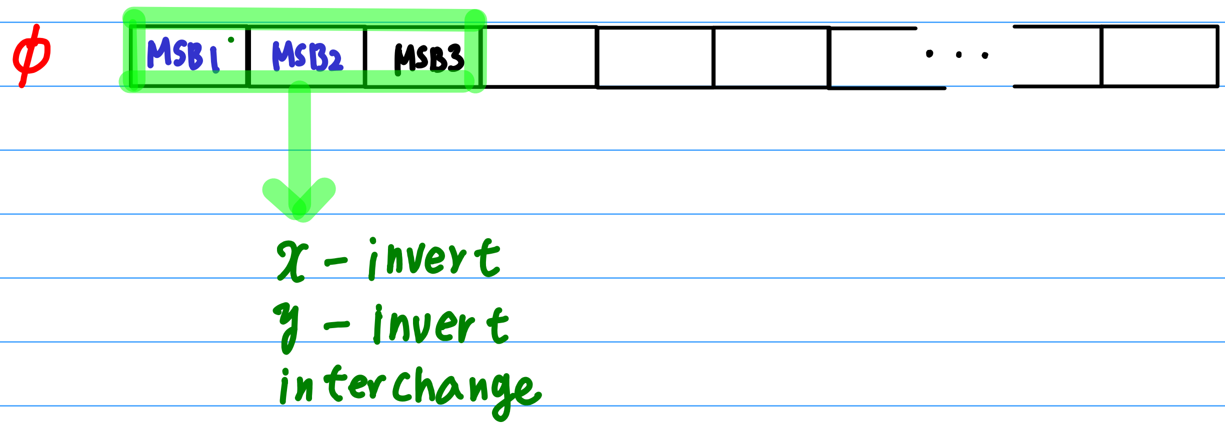
0.5	1	0	0	0	0	0	...	0
$\overline{\phi'}$	1	1	0	$\bar{a}_4$	$\bar{a}_5$	$\bar{a}_6$	...	$\bar{a}_N$

$0.5 - \phi'$	0	1	0	$\bar{a}_4$	$\bar{a}_5$	$\bar{a}_6$	...	$\bar{a}_N$
								+1

max	0	1	1	0	0	0	...	0

Control Signals : x invert, y invert, swap

normalized angle ϕ

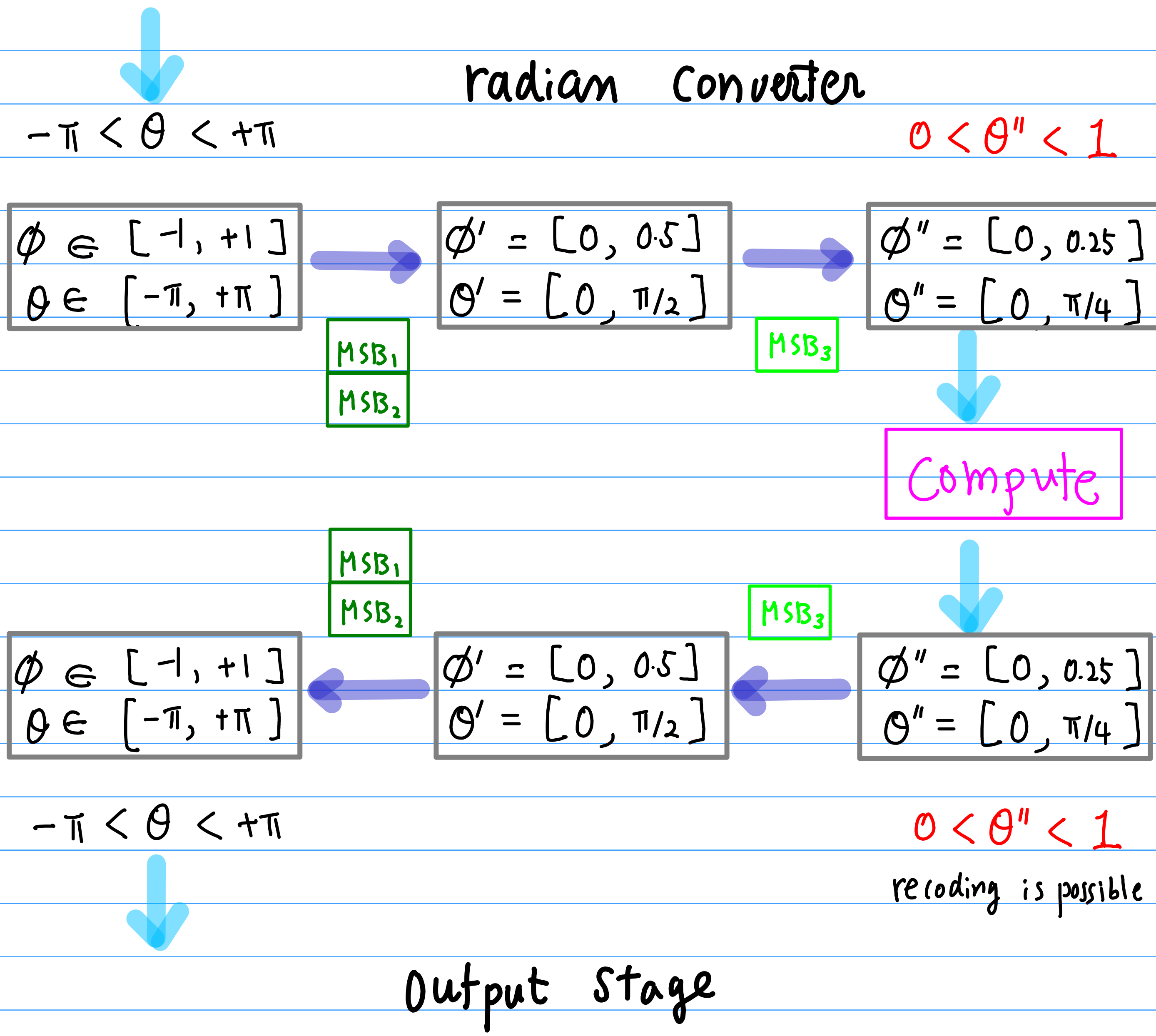


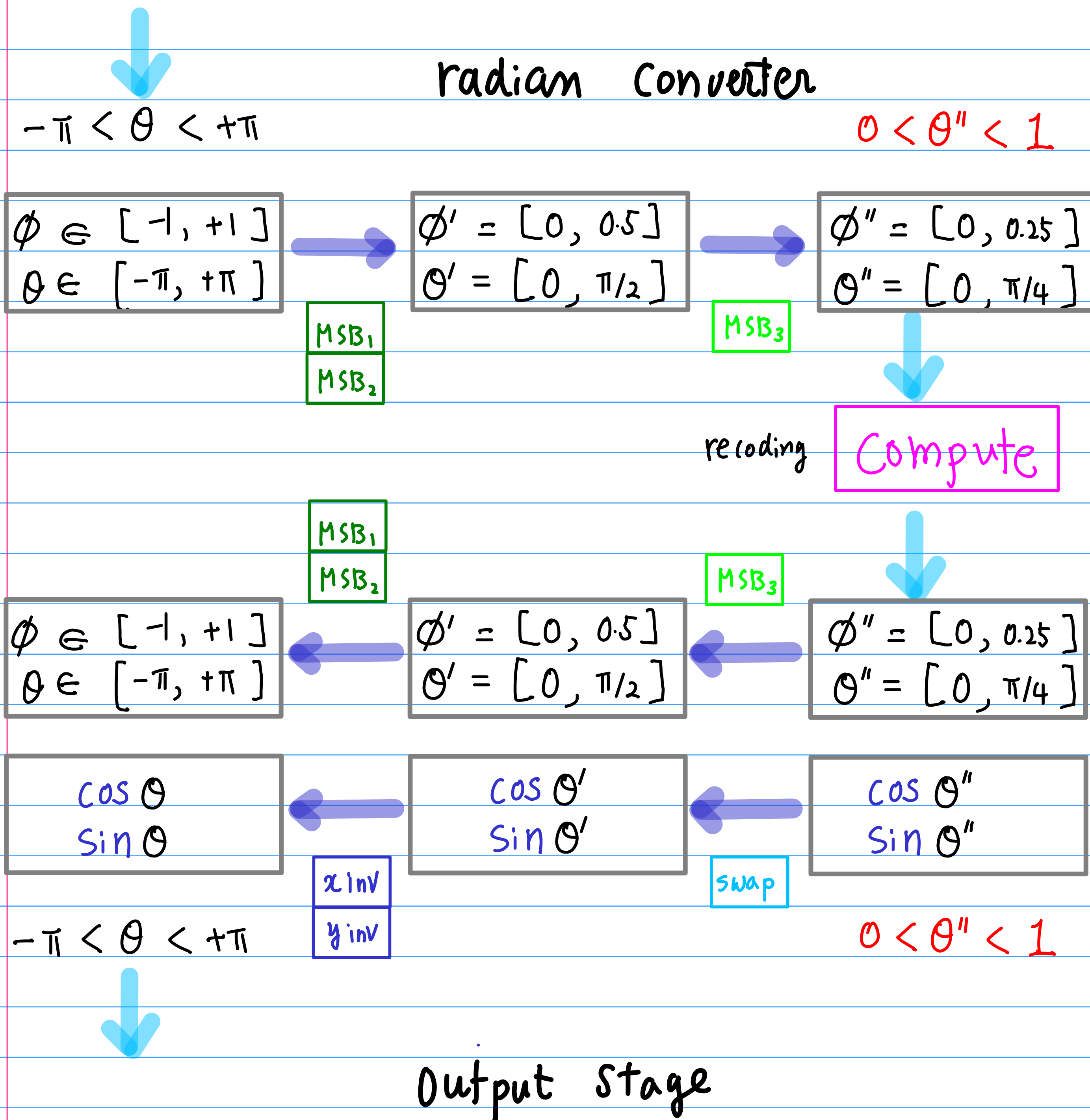
MSB1	MSB2	MSB3	x inv	y inv	swap
0	0	0	0	0	0
0	0	1	0	0	1
0	1	0	0	1	1
0	1	1	1	0	0
1	0	0	1	1	0
1	0	1	1	1	1
1	1	0	1	0	1
1	1	1	0	1	0

$\theta = \pi \phi \rightarrow \theta' = \pi \phi' \rightarrow \theta'' = \pi \phi''$

$\theta \in [-\pi, +\pi] \rightarrow \theta' = [0, \pi/2] \rightarrow \theta'' = [0, \pi/4]$

$\phi \in [-1, +1] \rightarrow \phi' = [0, 0.5] \rightarrow \phi'' = [0, 0.25]$




radian Converter
−π < θ < +π
0 < θ'' < 1
ϕ ∈ [−1, +1]
θ ∈ [−π, +π]
MSB1
MSB2
ϕ' = [0, 0.5]
θ' = [0, π/2]
MSB3
ϕ'' = [0, 0.25]
θ'' = [0, π/4]
recoding
Compute
MSB1
MSB2
MSB3
ϕ ∈ [−1, +1]
θ ∈ [−π, +π]
ϕ' = [0, 0.5]
θ' = [0, π/2]
ϕ'' = [0, 0.25]
θ'' = [0, π/4]
cos θ
sin θ
cos θ'
sin θ'
cos θ''
sin θ''
x inv
y inv
swap
−π < θ < +π
0 < θ'' < 1
Output Stage

$$\theta'' = \pi \phi''$$

radian angle $0 < \theta'' < \pi/4$

normalized angle $0 < \phi'' < 0.25$

$0 < \theta'' < 1$

The multiplication by π

→ could have used a **hardwired multiplier**

→ but don't have to use a multiplier at all

① in table lookup DDFS architecture

→ here, the multiplication by π is implicit

② in CORDIC architecture

the elementary angle are divided by π

$$\theta_k = \tan^{-1}(2^{-k}) / 2\pi$$

the direction of subrotations are determined by the sign of angle difference

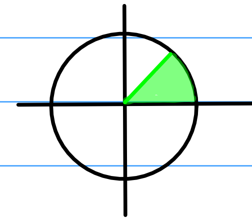
therefore the multiplication by π is not necessary

③ Sine / Cosine Generator

given angle θ (in radian)

$0 \leq \theta \leq \pi/4 < 1$

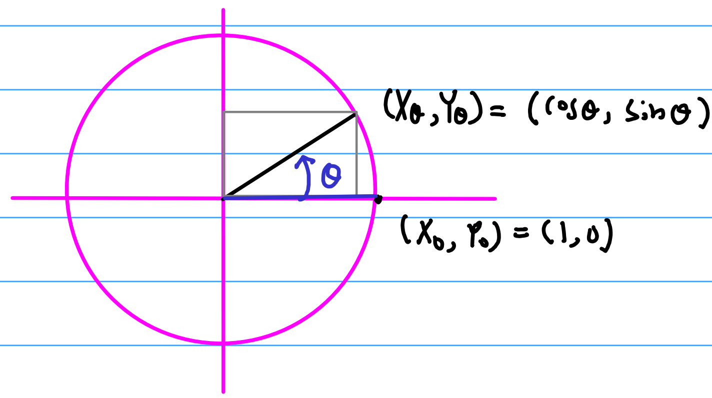
$\pi/4 \Rightarrow$ 0.785398163



compute $\cos\theta$, $\sin\theta$?

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$= \cos\theta \begin{bmatrix} 1 & -\tan\theta \\ \tan\theta & 1 \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$



$$\begin{bmatrix} \cos\theta \\ \sin\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$= \cos\theta \begin{bmatrix} 1 & -\tan\theta \\ \tan\theta & 1 \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$= \cos\theta \begin{bmatrix} 1 & -\tan\theta \\ \tan\theta & 1 \end{bmatrix} \begin{bmatrix} 1 \\ 0 \end{bmatrix}$$

a sequence of subrotations of the priori known angle

Suppose: θ as a sequence of sub-rotation

$\{\theta_k\}$ the subrotation angles are known a priori

then $\theta = \sigma_0 \theta_0 + \sigma_1 \theta_1 + \cdots + \sigma_N \theta_N$

$\sigma_k = \{-1, 0, +1\}$

① $\theta_k = \tan^{-1} 2^{-k}$ traditional CORDIC

② $\theta_k = 2^{-k}$ possible because $\theta'' < 1$

$$\theta = \sigma_0 \theta_0 + \sigma_1 \theta_1 + \cdots + \sigma_N \theta_N$$

$$\sigma_k = \{-1, 0, +1\}$$

$$\sigma_0 \theta_0 \rightarrow \cos(\sigma_0 \theta_0) \begin{bmatrix} 1 & -\tan(\sigma_0 \theta_0) \\ \tan(\sigma_0 \theta_0) & 1 \end{bmatrix}$$

$$\sigma_1 \theta_1 \rightarrow \cos(\sigma_1 \theta_1) \begin{bmatrix} 1 & -\tan(\sigma_1 \theta_1) \\ \tan(\sigma_1 \theta_1) & 1 \end{bmatrix}$$

$$\sigma_N \theta_N \rightarrow \cos(\sigma_N \theta_N) \begin{bmatrix} 1 & -\tan(\sigma_N \theta_N) \\ \tan(\sigma_N \theta_N) & 1 \end{bmatrix}$$

Sequence of sub-rotations

$$\theta = \sigma_0 \theta_0 + \sigma_1 \theta_1 + \cdots + \sigma_N \theta_N$$

$$\sigma_k = \{-1, 0, +1\}$$

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = \boxed{\cos(\sigma_0\theta_0)} \begin{bmatrix} 1 & -\tan(\sigma_0\theta_0) \\ \tan(\sigma_0\theta_0) & 1 \end{bmatrix} \boxed{\cos(\sigma_1\theta_1)} \begin{bmatrix} 1 & -\tan(\sigma_1\theta_1) \\ \tan(\sigma_1\theta_1) & 1 \end{bmatrix}$$
$$\cdots \boxed{\cos(\sigma_N\theta_N)} \begin{bmatrix} 1 & -\tan(\sigma_N\theta_N) \\ \tan(\sigma_N\theta_N) & 1 \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = K \begin{bmatrix} 1 & -\tan(\sigma_0\theta_0) \\ \tan(\sigma_0\theta_0) & 1 \end{bmatrix} \begin{bmatrix} 1 & -\tan(\sigma_1\theta_1) \\ \tan(\sigma_1\theta_1) & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\tan(\sigma_N\theta_N) \\ \tan(\sigma_N\theta_N) & 1 \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$K = \boxed{\cos(\sigma_0\theta_0)} \boxed{\cos(\sigma_1\theta_1)} \cdots \boxed{\cos(\sigma_N\theta_N)}$$ scale factor

$\sigma_k = +1$ positive angle rotation

$\sigma_k = -1$ negative angle rotation

A. CORDIC Algorithm

$$\theta = \sigma_0 \theta_0 + \sigma_1 \theta_1 + \cdots + \sigma_N \theta_N$$

$$\sigma_k = \{-1, 0, +1\}$$

$$\theta_k = \tan^{-1} 2^{-k}$$

$$\tan \theta_k = 2^{-k}$$

$$\tan(\sigma_k \theta_k) = (\sigma_k 2^{-k})$$

$$\sigma_k = \{-1, +1\}$$

$$K \begin{bmatrix} 1 & -\tan(\sigma_0\theta_0) \\ \tan(\sigma_0\theta_0) & 1 \end{bmatrix} \begin{bmatrix} 1 & -\tan(\sigma_1\theta_1) \\ \tan(\sigma_1\theta_1) & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\tan(\sigma_N\theta_N) \\ \tan(\sigma_N\theta_N) & 1 \end{bmatrix}$$

$$K = \cos(\sigma_0\theta_0)\cos(\sigma_1\theta_1)\cdots\cos(\sigma_N\theta_N)$$ scale factor

$$K \begin{bmatrix} 1 & -\sigma_0 2^{-0} \\ \sigma_0 2^{-0} & 1 \end{bmatrix} \begin{bmatrix} 1 & -\sigma_1 2^{-1} \\ \sigma_1 2^{-1} & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\sigma_N 2^{-N} \\ \sigma_N 2^{-N} & 1 \end{bmatrix}$$

↳ shift-and-add

$$K = \cos(\theta_0)\cos(\theta_1)\cdots\cos(\theta_N)$$

constant ← each rotation
+/− rotation
is actually performed

$$\begin{pmatrix} X_0 \\ Y_0 \end{pmatrix} = \begin{pmatrix} K \\ 0 \end{pmatrix}$$

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$= \begin{bmatrix} 1 & -\sigma_0 2^{-0} \\ \sigma_0 2^{-0} & 1 \end{bmatrix} \begin{bmatrix} 1 & -\sigma_1 2^{-1} \\ \sigma_1 2^{-1} & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\sigma_N 2^{-N} \\ \sigma_N 2^{-N} & 1 \end{bmatrix} \begin{bmatrix} K \\ 0 \end{bmatrix}$$

$$K = \cos(\theta_0) \cos(\theta_1) \cdots \cos(\theta_N)$$

σ_k determines pos / neg subrotation by an angle θ_k

σ_k values are determined iteratively by the successive approximation

at the k-th iteration

- if the current appraximation $>$ the input angle θ then subtract θ_k
- if the current appraximation $<$ the input angle θ then add θ_k

CORDIC HW → $\frac{1}{3}$ of the total HW

ⓐ computes σ_k
updates the current approximation by the angle θ_k

ⓑ performs the rotation by θ_k

(addition
comparison)

redundant CSA — addition — $\sum \theta_k$
eliminates the carry propagate delay
improves the throughput

the evaluation of each σ_k — comparison
requires the knowledge of the sign difference
between two angles

the sign detection in redundant arithmetic
non-trivial, bottleneck

B. Recoding Algorithm

$$\theta = \sigma_0 \theta_0 + \sigma_1 \theta_1 + \cdots + \sigma_N \theta_N .$$

$$\sigma_k = \{-1, 0, +1\}$$

$$\theta_k = 2^{-k}$$

$$\tan \theta_k = \tan 2^{-k}$$

$$\tan(\sigma_k \theta_k) = \tan(\sigma_k 2^{-k})$$

$$\sigma_k = \{-1, +1\}$$

$$\begin{bmatrix} X_\theta \\ Y_\theta \end{bmatrix} = \begin{bmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix} = \cos\theta \begin{bmatrix} 1 & -\tan\theta \\ \tan\theta & 1 \end{bmatrix} \begin{bmatrix} X_0 \\ Y_0 \end{bmatrix}$$

$$K \begin{bmatrix} 1 & -\tan(\sigma_0\theta_0) \\ \tan(\sigma_0\theta_0) & 1 \end{bmatrix} \begin{bmatrix} 1 & -\tan(\sigma_1\theta_1) \\ \tan(\sigma_1\theta_1) & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\tan(\sigma_N\theta_N) \\ \tan(\sigma_N\theta_N) & 1 \end{bmatrix}$$

$$K = \cos(\sigma_0\theta_0)\cos(\sigma_1\theta_1)\cdots\cos(\sigma_N\theta_N)$$ scale factor

$$\theta = \sigma_0 \theta_0 + \sigma_1 \theta_1 + \cdots + \sigma_N \theta_N \qquad \sigma_k \in \{-1, 0, +1\}$$

$$\theta'' = \boxed{\sum_{k=1}^{N} b_k \cdot 2^{-k} = \phi_0 + \sum_{k=2}^{N+1} r_k \cdot 2^{-k}} \qquad \begin{matrix} b_k \in \{0, 1\} \\ r_k \in \{-1, +1\} \end{matrix}$$

$$K \begin{bmatrix} 1 & -\tan(\sigma_0 \theta_0) \\ \tan(\sigma_0 \theta_0) & 1 \end{bmatrix} \begin{bmatrix} 1 & -\tan(\sigma_1 \theta_1) \\ \tan(\sigma_1 \theta_1) & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\tan(\sigma_N \theta_N) \\ \tan(\sigma_N \theta_N) & 1 \end{bmatrix}$$

$$K = \cos(\theta_0) \cos(\theta_1) \cdots \cos(\theta_N) \qquad \theta_k = \tan^{-1} 2^{-k}$$

$$K \begin{bmatrix} 1 & -\tan(r_2 \theta_2) \\ \tan(r_2 \theta_2) & 1 \end{bmatrix} \begin{bmatrix} 1 & -\tan(r_3 \theta_3) \\ \tan(r_3 \theta_3) & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\tan(r_N \theta_N) \\ \tan(r_N \theta_N) & 1 \end{bmatrix}$$

$$K = \cos(\theta_2) \cos(\theta_3) \cdots \cos(\theta_N) \qquad \theta_k = 2^{-k}$$

The recoding maintains a constant scale factor K

$$K \begin{bmatrix} 1 & -\tan(r_2\theta_2) \\ \tan(r_2\theta_2) & 1 \end{bmatrix} \begin{bmatrix} 1 & -\tan(r_3\theta_3) \\ \tan(r_3\theta_3) & 1 \end{bmatrix} \cdots \begin{bmatrix} 1 & -\tan(r_N\theta_N) \\ \tan(r_N\theta_N) & 1 \end{bmatrix}$$

$$K = \cos(\theta_2)\cos(\theta_3)\cdots\cos(\theta_N) \qquad \theta_k = 2^{-k}$$

$$\begin{bmatrix} X_{k+1} \\ Y_{k+1} \end{bmatrix} = \begin{bmatrix} 1 & -\tan(r_k\theta_k) \\ \tan(r_k\theta_k) & 1 \end{bmatrix} \begin{bmatrix} X_k \\ Y_k \end{bmatrix} = \begin{bmatrix} X_k - \tan(r_k\theta_k) Y_k \\ Y_k + \tan(r_k\theta_k) X_k \end{bmatrix}$$

Sub rotation

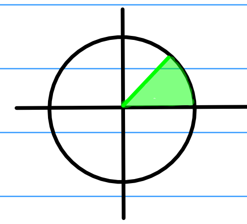
$$X_{k+1} = X_k - \tan(r_k\theta_k) Y_k$$
$$Y_{k+1} = Y_k + \tan(r_k\theta_k) X_k$$

Angle Recoding

given angle θ (in radian)

$0 \leq \theta \leq \pi/4 < 1$

$\pi/4 \Rightarrow$ 0.785398163



$$\theta = \sum_{k=1}^{N} b_k \theta_k$$ Binary Representation

$b_k \in \{0, 1\}$

$\theta_k = 2^{-k}$

(N+1) bit fractional binary

Sign + N bit $\Rightarrow$ | S | b_1 b_2 $\cdots$ b_N |

assume θ is positive $\quad b_0 = 0 \quad S = 0$

$$\theta = \sum_{k=1}^{N} b_k 2^{-k} = \phi_0 + \sum_{k=2}^{N+1} r_k 2^{-k}$$

$r_k \in \{-1, +1\}$ signed digits

ϕ_0 constant

(+) subrotation by 2^{-k}

2 equal half rotations by 2^{-k-1}

(+)(+)

(0) subrotation

2 equal opposite half rotations by $\pm 2^{-k-1}$

(+)(−) (−)(+)

Binary Representation

$b_k = 1$: rotation by 2^{-k}

$b_k = 0$: zero rotation

⋮

	fixed		
k-th rotation	pos 2^{-k-1} rotation	pos 2^{-k-1} rotation	← $b_k = 1$
	pos 2^{-k-1} rotation	neg 2^{-k-1} rotation	← $b_k = 0$

⋮

Combining all the fixed rotations

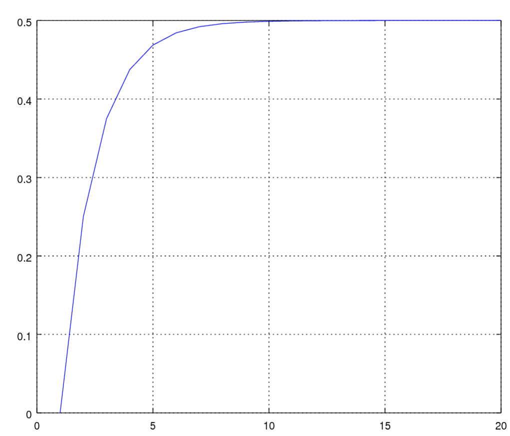
→ initial fixed rotation

	b_1 2^{-1}	b_2 2^{-2}	b_3 2^{-3}		b_N 2^{-N}
fixed ⇒	$+2^{-2}$	$+2^{-3}$	$+2^{-4}$		$+2^{-N-1}$
	$(b_1=1)$ $+2^{-2}$	$(b_2=1)$ $+2^{-3}$	$(b_3=1)$ $+2^{-4}$		$(b_N=1)$ $+2^{-N-1}$
	$(b_1=0)$ -2^{-2}	$(b_2=0)$ -2^{-3}	$(b_3=0)$ -2^{-4}		$(b_N=0)$ -2^{-N-1}

initial fixed rotation

$$\phi_0 = \frac{1}{2^2} + \frac{1}{2^3} + \cdots + \frac{1}{2^{N+1}}$$

$$= \frac{\frac{1}{2^2}\left(1-\frac{1}{2^N}\right)}{\left(1-\frac{1}{2}\right)} = \frac{1}{2}\left(1-\frac{1}{2^N}\right) = \frac{1}{2} - \frac{1}{2^{N+1}}$$



Signed Digit Recoding

the rotation after recoding

— a fixed initial rotation ϕ_0

a sequence of ⊕/⊖ rotations

$b_k = 1$ $+ 2^{-k-1}$ rotation
$b_k = 0$ $- 2^{-k-1}$ rotation

$r_k = (2b_{k-1} - 1)$

$2 \cdot 1 - 1 = +1$ $b_{k-1} = 1 \longrightarrow r_k = +1$
$2 \cdot 0 - 1 = -1$ $b_{k-1} = 0 \longrightarrow r_k = -1$

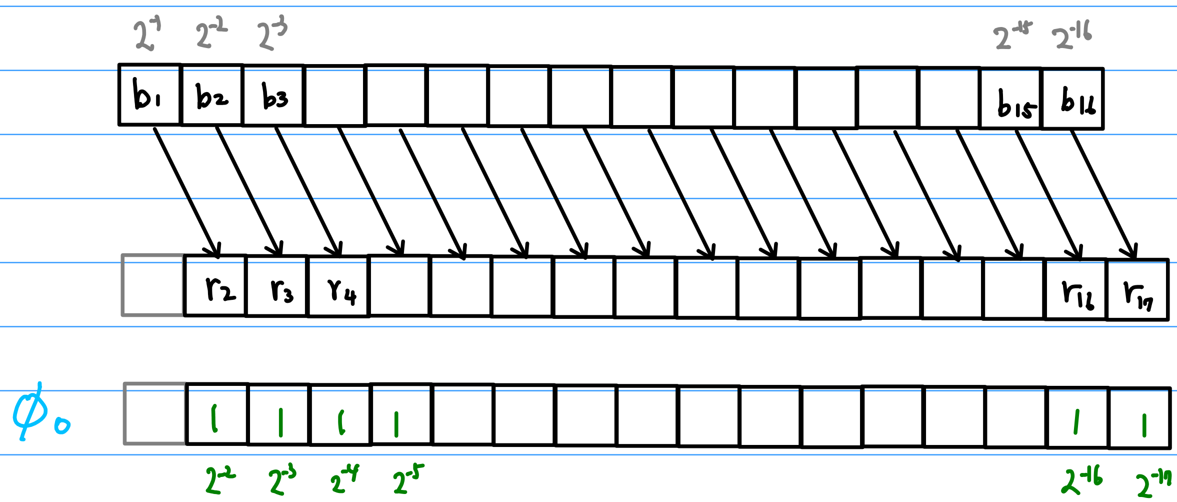
The recoding need not be explicitly performed

Simply replacing $b_k = 0$ with -1

This recoding maintains
a constant scaling factor K

$$\theta = \sum_{k=1}^{N} b_k 2^{-k} = \phi_0 + \sum_{k=2}^{N+1} r_k 2^{-k}$$

Binary Representation $\{b_k\}$



Signed Digit Recoding $\{r_k\}$

MSB$_1$ | MSB$_2$ | MSB$_3$ → $0 < \theta'' < 1$ → recoding $\{r_k\}$

$$\sum_{k=1}^{N} b_k \cdot 2^{-k} = \phi_0 + \sum_{k=2}^{N+1} r_k \cdot 2^{-k}$$

$b_k \in \{0, 1\}$ $r_k \in \{-1, +1\}$

$$\begin{cases} b_k = 1 \rightarrow r_{k+1} = +1 \\ b_k = 0 \rightarrow r_{k+1} = -1 \end{cases}$$

$$r_k = (2b_{k-1} - 1)$$

ϕ_0 depends only on bit width N

for fixed N, $\phi_0 = \frac{1}{2} - \frac{1}{2^{N+1}}$ is a constant

The Scaling K.

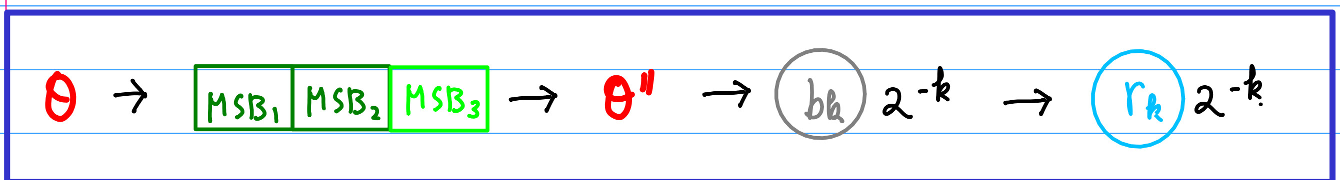
The initial rotation $\phi_0 = \frac{1}{2} - \frac{1}{2^{N+1}}$

rotation starting point

$$(X_0, Y_0) = (K\cos\phi_0,\ K\sin\phi_0)$$

rotation always starts from this fixed point.

Cascade of feed forward rotational stages



binary representation

recoding

{ no comparison
no error build up

① $\theta_k = \tan^{-1} 2^{-k}$ traditional CORDIC

☆ ② $\theta_k = 2^{-k}$ possible because $\theta'' < 1$

$$\begin{bmatrix} 1 & -\sigma_k \tan(2^{-k}) \\ \sigma_k \tan(2^{-k}) & 1 \end{bmatrix}$$

④ Output stage

$$-\pi < \theta = \pi\phi < \pi$$

$$0 < \theta'' = \pi\phi'' < \frac{\pi}{4}$$

$X_{N+1} = \cos\theta'' \longrightarrow \cos\theta$

$Y_{N+1} = \sin\theta'' \longrightarrow \sin\theta$

$\theta'' \in [0, \frac{\pi}{4}]$ $\theta \in [-\pi, +\pi]$

Output stage

$\sin\theta \longrightarrow \sin\pi\phi$

$\cos\theta \longrightarrow \cos\pi\phi$

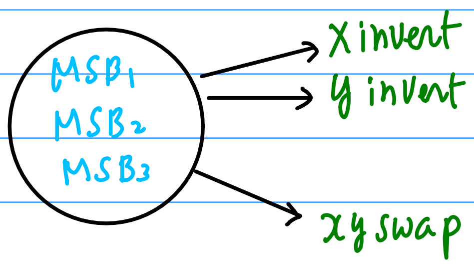
$[-\pi, +\pi]$

$\sin\theta'' \longrightarrow \sin\theta$

$\cos\theta'' \longrightarrow \cos\theta$

$[0, \frac{\pi}{4}]$ $\quad [-\pi, +\pi]$

negation / interchange



the negation of

$\cos\theta'' = X_{N+1}$

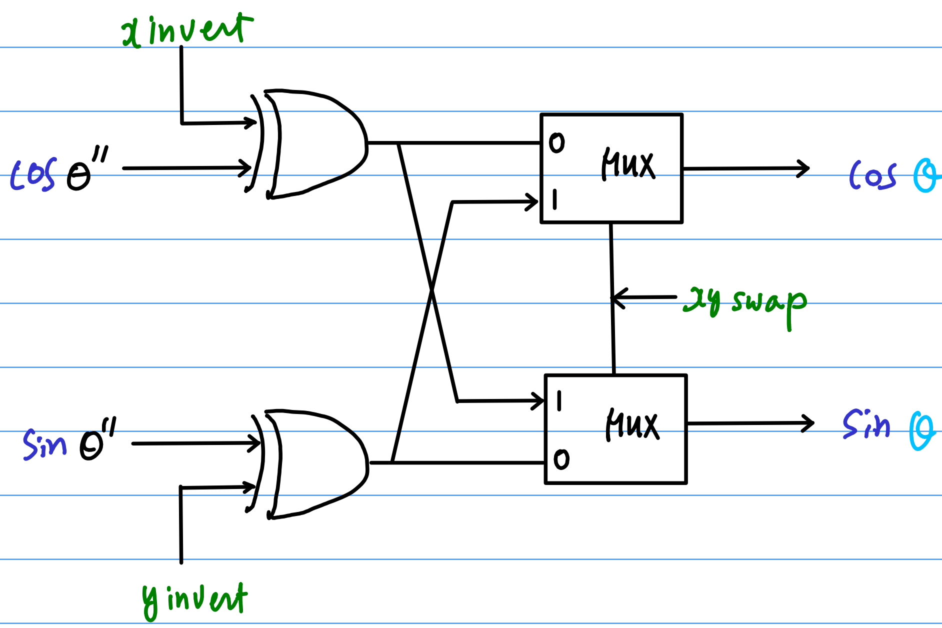
$\sin\theta'' = Y_{N+1}$

interchange

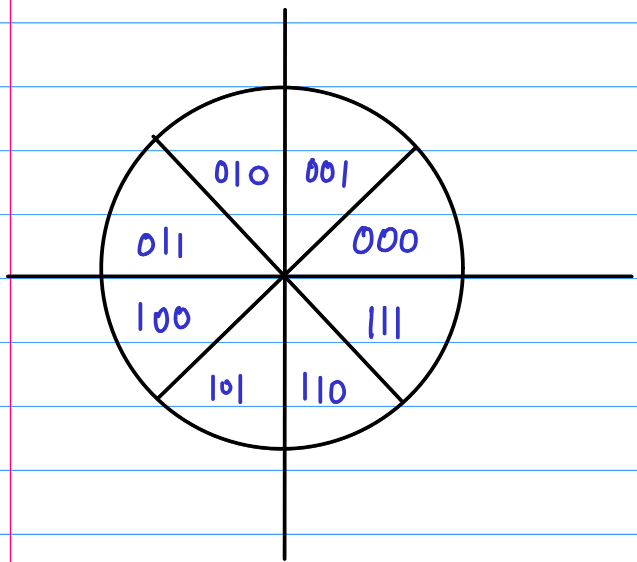
$\cos\theta'' = X_{N+1}$

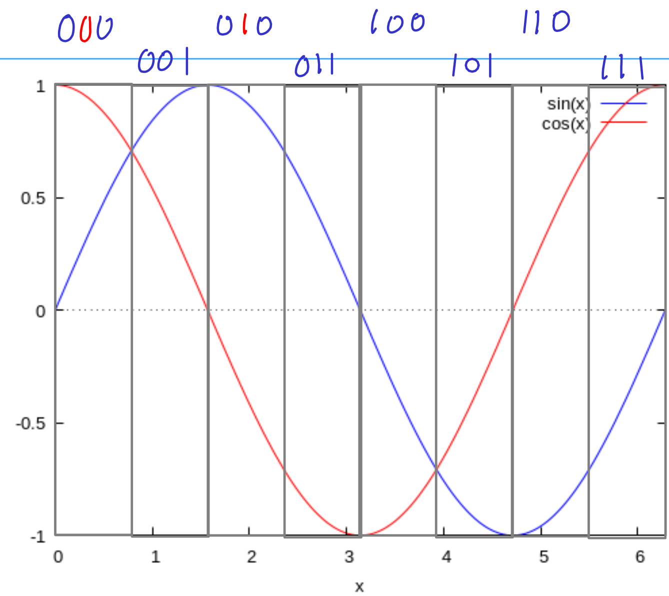
$\sin\theta'' = Y_{N+1}$

negate before swap



$\theta'' \in [0, \frac{\pi}{4}]$ $\qquad \theta \in [-\pi, +\pi]$



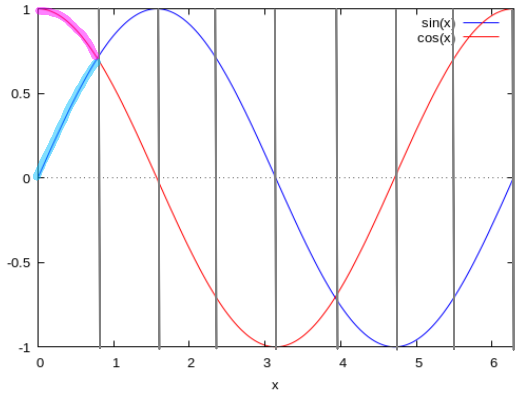


	cos	sin.			
	x inv	y inv	swap	$\cos\pi\theta$	$\sin\pi\phi$
0 0 0	0	0	0	$\cos\theta$	$\sin\theta$
0 0 1	0	0	1	$\sin\theta$	$\cos\theta$
0 1 0	0	1	1	$-\sin\theta$	$\cos\theta$
0 1 1	1	0	0	$-\cos\theta$	$\sin\theta$
1 0 0	1	1	0	$-\cos\theta$	$-\sin\theta$
1 0 1	1	1	1	$-\sin\theta$	$-\cos\theta$
1 1 0	1	0	1	$\sin\theta$	$-\cos\theta$
1 1 1	0	1	0	$\cos\theta$	$-\sin\theta$

(0)

$\cos\theta$

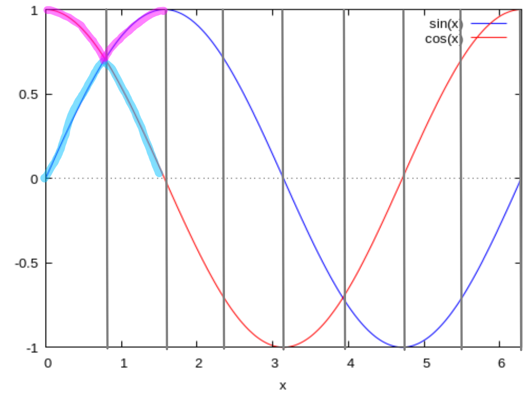
$\sin\theta$



(1)

$\sin\theta$

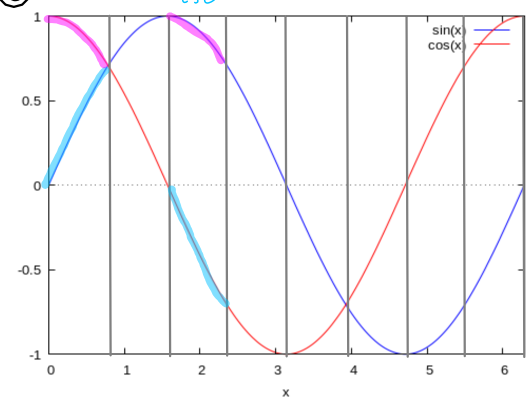
$\cos\theta$



(2)

$-\sin\theta$

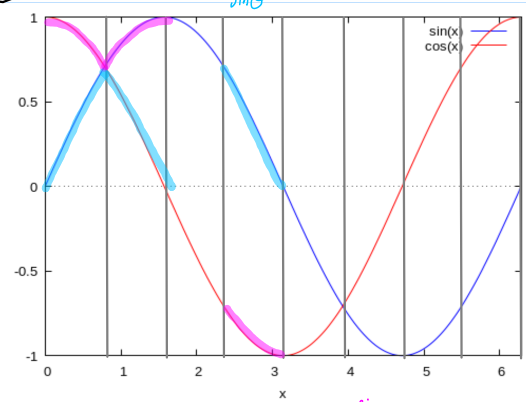
$\cos\theta$



(3)

$-\cos\theta$

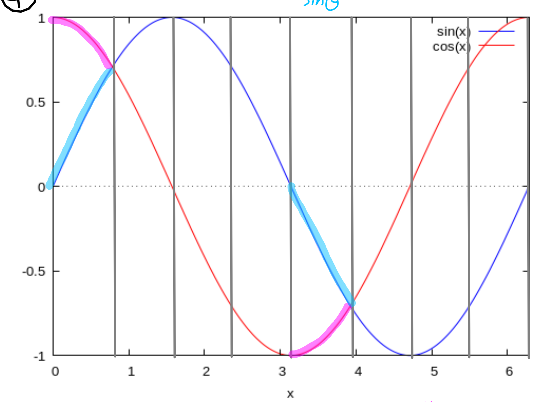
$\sin\theta$



(4)

$-\cos\theta$

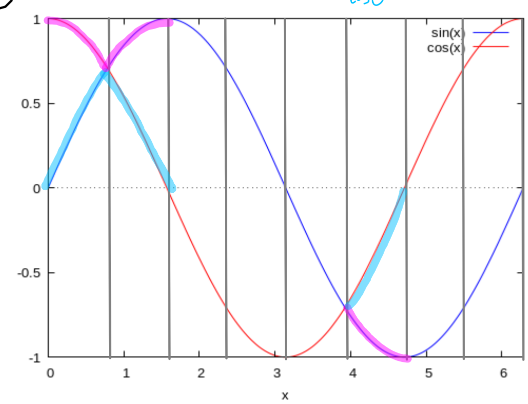
$-\sin\theta$



(5)

$-\sin\theta$

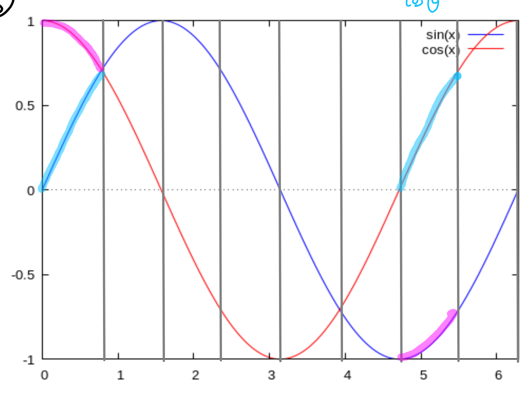
$-\cos\theta$



(6)

$\sin\theta$

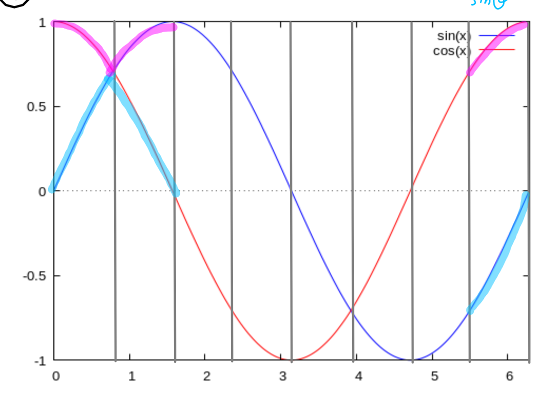
$-\cos\theta$



(7)

$\cos\theta$

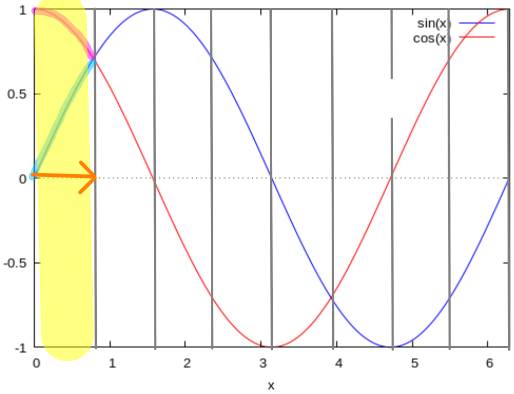
$-\sin\theta$



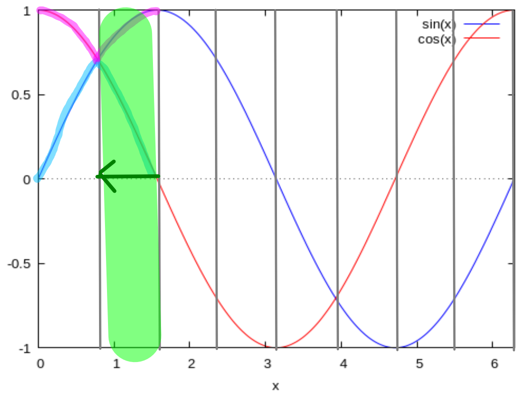
Madisetti & Willson, DDS Freq synthesizer

{ cos Φ
  sin Φ

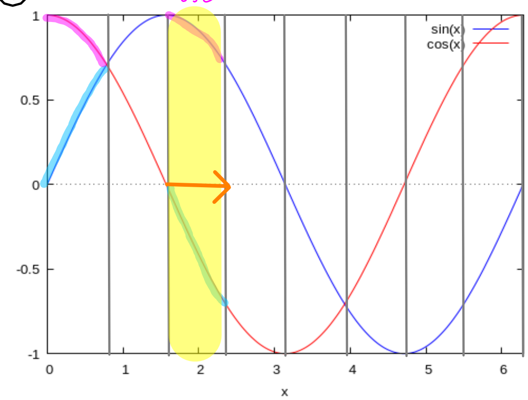
⓪ cos θ / sin θ



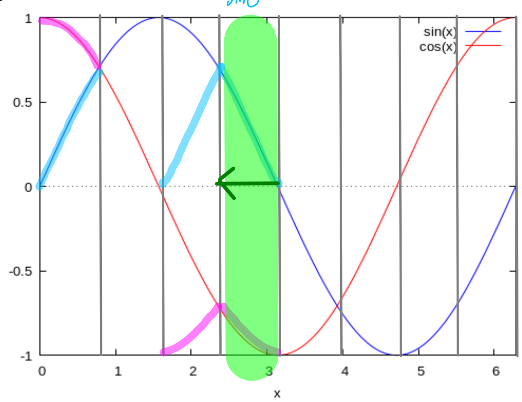
① sin θ / cos θ)



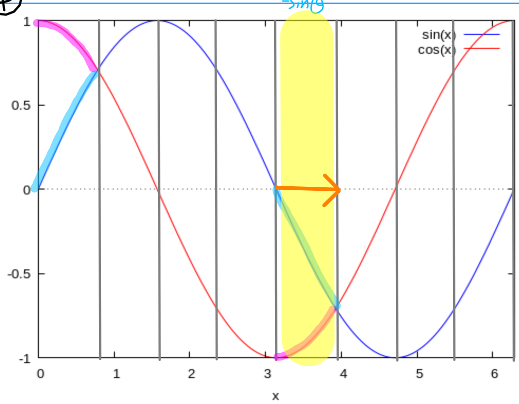
② -sin θ / cos θ)



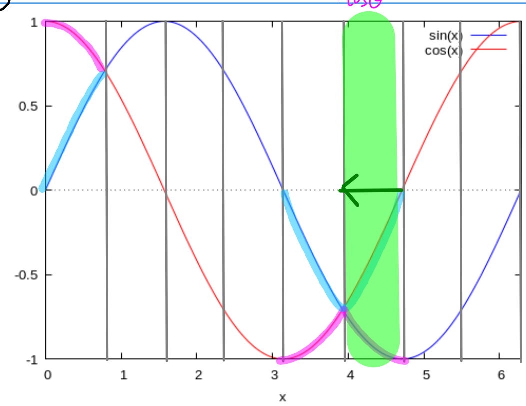
③ -cos θ / sin θ



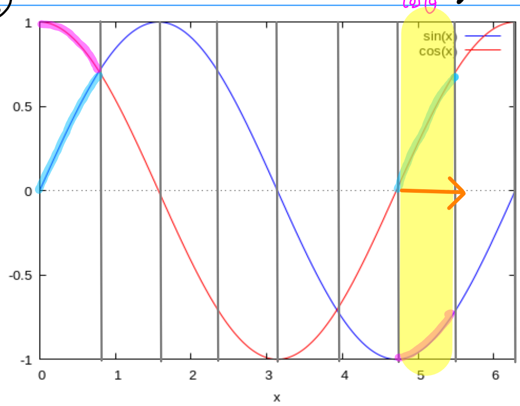
④ -cos θ / -sin θ



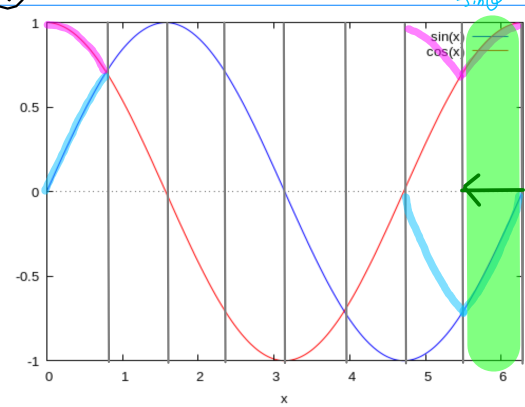
⑤ -sin θ / -cos θ)



⑥ sin θ / -cos θ)

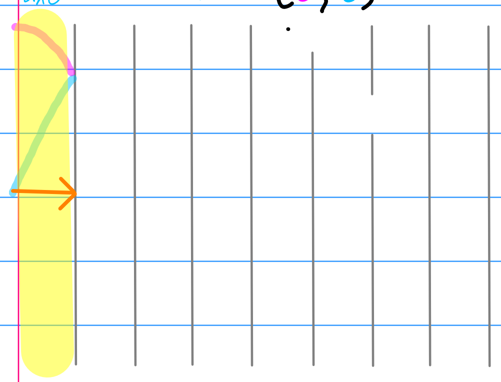


⑦ cos θ / -sin θ

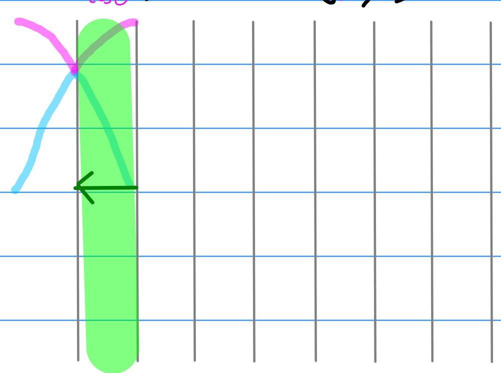


sin Φ

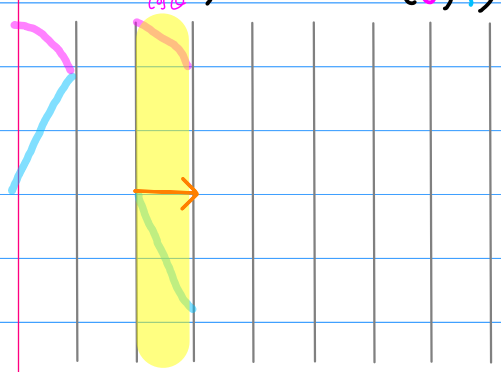
⓪ cos θ / sin θ   + +   (0, 0)



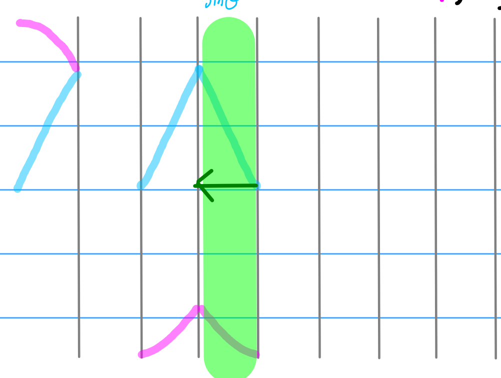
① sin θ) / cos θ   + +   (0, 0)



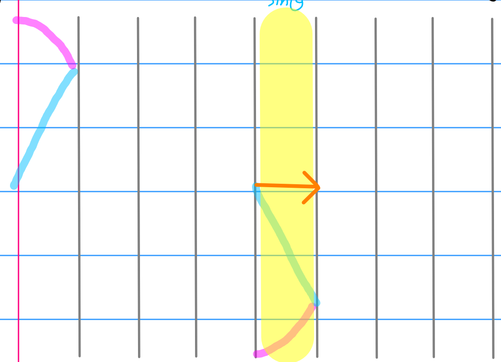
② -sin θ) / cos θ   + -   (0, 1)



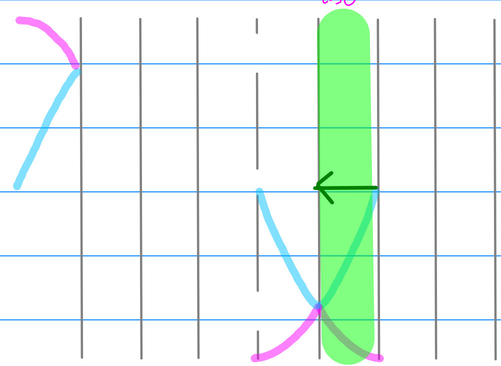
③ -cos θ / sin θ   - +   (1, 0)



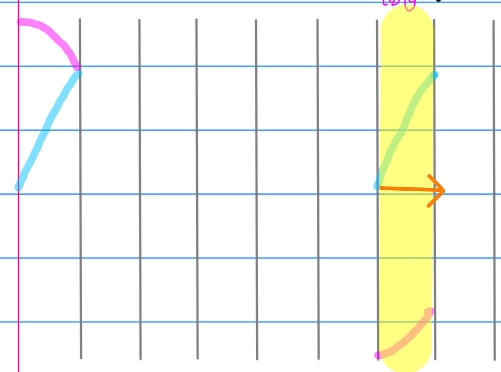
④ -cos θ / -sin θ   - -   (1, 1)



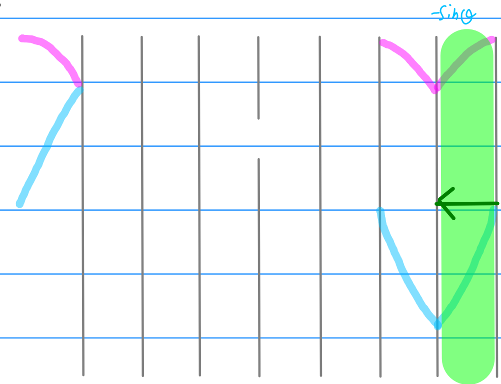
⑤ -sin θ) / -cos θ   - -   (1, 1)



⑥ sin θ) / -cos θ   - +   (1, 0)



⑦ cos θ / -sin θ   + -   (0, 1)



	Xinv	Yinv	swap	$\cos \pi\phi$	$\sin \pi\phi$
0 0 0	0	0	0	$\cos\theta$	$\sin\theta$
0 0 1	0	0	1	$\sin\theta$	$\cos\theta$
0 1 0	0	1	1	$-\sin\theta$	$\cos\theta$
0 1 1	1	0	0	$-\cos\theta$	$\sin\theta$
1 0 0	1	1	0	$-\cos\theta$	$-\sin\theta$
1 0 1	1	1	1	$-\sin\theta$	$-\cos\theta$
1 1 0	1	0	1	$\sin\theta$	$-\cos\theta$
1 1 1	0	1	0	$\cos\theta$	$-\sin\theta$

0	0 0	0 0	0
1	0 1	1 0	1
3	1 1	1 1	3
2	1 0	0 1	2

0 0   0 0

0 1   0 1

1 1   1 1

1 0   1 0