Angle Recording CORDIC

1. Hu

20180529

Copyright (c) 2015 - 2016 Young W. Lim.
Permission is granted to copy, distribute and/or modify this document under the terms of the GNU Free Documentation License, Version 1.2 or any later version published by the Free Software Foundation; with no Invariant Sections, no Front-Cover Texts, and no Back-Cover Texts. A copy of the license is included in the section entitled "GNU Free Documentation License".

to reduce the number of CORDIC iterations

by encoding the angle of rotation
as a linear combination of
selected elementary angle of micro-rotations

Signal / Image processing DFT & DCT
- the rotation angle known a priori

greedy algorithms to perform angle recoding

linear combination of
elementary rotation angles

FFT, Chirp-z

a circular rotation

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} \cos\theta & \sin\theta \\ -\sin\theta & \cos\theta \end{bmatrix} \begin{bmatrix} x \\ y \end{bmatrix}$$

$\cos\theta$, $\sin\theta$

CORDIC : a sequence of successive rotation

n elementary rotation angles

$a(i)$, $i = 0, \cdots, n-1$

$\tan[a(i)] = 2^{-i}$

only shifts and adds operations

$$\theta = \sum_{i=0}^{n-1} u(i)\, a(i) + \varepsilon$$

ε : an angle approximation error

$$|\varepsilon| \leqslant a(n-1)$$

the direction of rotation angle

$$u(i) = +1 \text{ or } -1$$

$$z(0) = \theta$$

$$z(i+1) = z(i) - u(i)\, a(i) \qquad i = 0, \cdots, n-1$$

$$u(i) = \mathrm{sign}(z(i))$$

Initialization $x(0) = x$
$y(0) = y$

For $i = 0$ to $n-1$ do
CORDIC Rotation

$$\begin{bmatrix} x(i+1) \\ y(i+1) \end{bmatrix} = \begin{bmatrix} 1 & \tan u(i)a(i) \\ -\tan u(i)a(i) & 1 \end{bmatrix} \begin{bmatrix} x(i) \\ y(i) \end{bmatrix}$$

Scaling operation

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \prod_{i=0}^{n-1} \cos u(i)a(i) \cdot \begin{bmatrix} x(n) \\ y(n) \end{bmatrix}$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} \leftarrow \begin{bmatrix} x(n) \\ y(n) \end{bmatrix} \leftarrow \cdots \leftarrow \begin{bmatrix} x(1) \\ y(1) \end{bmatrix} \leftarrow \begin{bmatrix} x(0) \\ y(0) \end{bmatrix}$$

shift and add operations

$$\prod_{i=0}^{n-1} \cos u(i)a(i) = \frac{1}{K(n)}$$ norm correction

a known constant
once the set $\{u(i)a(i) : i = 0, \cdots, n-1\}$
is determined

a multiplier recoding method
can be applied
Booth's algorithm

For convenience, assume

$|\theta| < 2a(0) = \frac{\pi}{2}$

ⓐ if $\theta > 2\pi$, $\theta \leftarrow \theta \bmod 2\pi$

ⓑ if $2\pi > \theta > \pi$, $\begin{bmatrix} x \\ y \end{bmatrix} \leftarrow \begin{bmatrix} -x \\ -y \end{bmatrix}$, $\theta \leftarrow \theta - \pi$

ⓒ if $\pi > \theta > \frac{\pi}{2}$ $\begin{bmatrix} x \\ y \end{bmatrix} \leftarrow \begin{bmatrix} y \\ -x \end{bmatrix}$, $\theta \leftarrow \theta - \frac{\pi}{2}$

CORDIC Angle Recoding Problem

$u(i) = 0$ is allowed. repetition

$$u(i) = \begin{cases} +1 \\ 0 \\ -1 \end{cases}$$

desirable to minimize $\sum_{i=0}^{n-1} |u(i)|$

$\rightarrow$ reduce CORDIC iterations

Angle Recoding

given $a(i)$, $i=0, \cdots, n-1$
θ an angle

find $u(i)$, $i=0, \cdots, n-1$ $\quad u(i) \in \{-1, 0, +1\}$

such that

(i) $\theta = \sum_{i=0}^{n-1} u(i)\, a(i) + \varepsilon \qquad \varepsilon < a(n-1)$

(ii) $\sum_{i=0}^{n-1} |u(i)|$ is minimized

CORDIC Angle Recoding Algorithm

Initialization : $\theta(0) = \theta$, $\{u(i) = 0,\ 0 \le i \le n-1\}$, $k = 0$

Repeat until $|\theta(k)| < a(n-1)$ Do

① choose i_k, $0 \le i_k \le n-1$ such that

$$\big|\,|\theta(k)| - a(i_k)\big| = \min_{0 \le i \le n-1} \big|\,|\theta(k)| - a(i)\big|$$

② $\theta(k+1) = \theta(k) - u(i_k)a(i_k)$

$u(i_k) = \text{sign}(\theta(k))$

greedy

Elementary Angle Set

$S = \{ (\sigma \cdot \tan^{-1}(2^{-r})) : \sigma \in \{+1, -1\}, \ r \in \{1, 2, \cdots, n-1\} \}$

n-bit angle as a linear combination

$$\theta = \sum_{i=0}^{n-1} \sigma_i \cdot \tan^{-1}(2^{-i})$$

AR : $\sigma \in \{-1, 0, +1\}$

EAS (Elementary Angle Set) for AR methods

$S_{EAS} = \{ (\sigma \cdot \tan^{-1}(2^{-r})) : \sigma \in \{+1, 0, -1\}, \ r \in \{1, 2, \cdots, n-1\} \}$

Simple angle recording — Hu's greedy algorithm

tries to represent the remaining angle using the closest elementary angle $\pm \tan^{-i}$

$\left\{ \begin{array}{l} \text{rotation mode — Angle Recording} \\ \text{vectoring mode — Backward Angle Recording (BAR)} \end{array} \right.$

initialize $\theta_0 = \theta$

$\sigma_i = 0 \qquad i = 0, 1, \cdots, n-1$

$k = 0$

repeat until $|\theta_k| < \tan^{-1}(2^{-n+1})$ do

1. choose i_k, $\quad i_k = 0, 1, 2, \cdots, n-1$
   such that
   $$\left|\, |\theta_k| - \tan^{-1}(2^{-i_k}) \,\right| = \min_{i \in [0:n-1]} \left|\, |\theta_k| - \tan^{-1}(2^{-i}) \,\right|$$

2. $$\theta_{k+1} = \theta_k - \sigma_{i_k} \tan^{-1}(2^{-i_k})$$
   $$\sigma_{i_k} = \mathrm{sign}(\theta_k)$$