

TI Designs: TIDEP-01003

采用毫米波传感器的区域占位检测参考设计



说明

TIDEP-01003 展示了 TI 的单芯片毫米波 (mmWave) 技术如何用于区域占位检测。对进入所关注区域之人员或物体的移动的检测可用于区域扫描仪和停车位监测。区域占位检测系统可监测 ± 60 度视野内所关注的区域, 最大距离为 10m。该参考设计使用 IWR1443BOOST 评估模块 (EVM) 并在 IW443 器件中集成了完整的雷达处理链。该处理链包含模拟雷达配置、模数转换器 (ADC) 捕捉、低级 FFT 和信号处理。该参考设计构建在 TI 毫米波 SDK 基础之上, 用于实现集中的软件体验, 其中包括用于评估、开发和数据可视化的 API、库和工具。

资源

TIDEP-01003	设计文件夹
IWR1443	产品文件夹
IWR1443BOOST	工具文件夹
毫米波 SDK	工具文件夹

特性

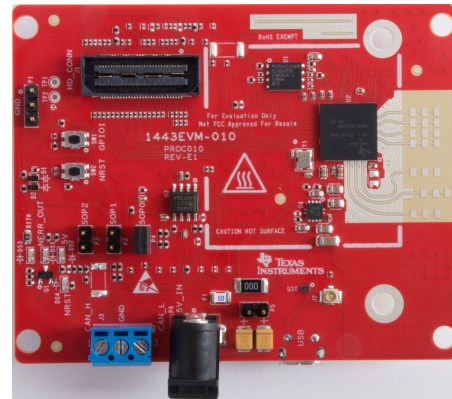
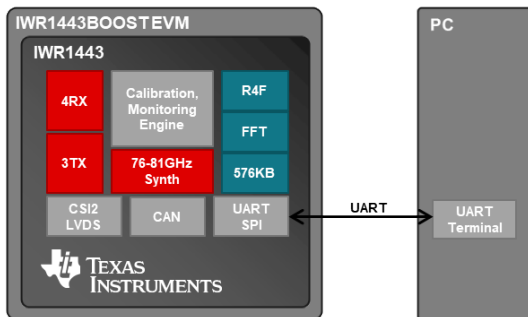
- 演示使用 TI 的单芯片毫米波传感器实现环境稳定型区域占位检测
- 检测视野高达 120° 的所关注区域内的物体或人员入侵, 距离范围为 0m 至 10m
- 引用根据毫米波软件开发套件 (SDK) 提供的处理链源代码
- 基于成熟的 EVM 硬件设计, 可缩短上市时间并支持开箱即用演示

应用

- [区域扫描仪安全防护装置](#)
- [接近传感器](#)
- [光幕安全防护装置](#)
- [运输用雷达](#)



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1 System Description

The TIDEP-01003 provides a reference for creating a zone occupancy detection application using TI's IWR1443, based on 77-GHz mmWave radio-frequency complementary metal-oxide semiconductor (RF-CMOS) technology. Frequency-modulated continuous-wave (FMCW) radars enable accurate measurement of distances and relative velocities. Thus, radars are useful for detection of occupancy and whether an object or person has entered a space of interest.

In area scanner or light curtain safety-guard applications, where it is important to have precisely defined "keep-out" zones, the ability of radar to accurately localize detected objects can be used to implement multiple detection zones and trigger corresponding responses. A single radar deployed to equipment with a critical "keep-out" perimeter could implement a multi-stage response, so that when an object or person first approaches the perimeter, a moderate warning flag is raised. Then, if the perimeter is breached, a critical response is triggered.

Similarly, in parking spot occupancy applications, a mmWave radar device can monitor multiple parking spots. With each parking spot comprising a zone, the zone occupancy detection system can detect whether or not a spot is occupied by a vehicle.

An important advantage of radars over camera and light-detection-and-ranging (LIDAR)-based systems is that radars are relatively immune to environmental conditions such as rain, dust, and smoke. Because FMCW radars transmit a specific signal (called a chirp) and process the reflections, they can work in both complete darkness and bright daylight (radars are not affected by glare). When compared with ultrasound, radars typically have a much longer range and faster transit time for their signals.

表 1. Key System Specifications

PARAMETER	SPECIFICATIONS	DETAILS
Field of view (FOV)	120° azimuth, 30° elevation	The field of view of the sensor is determined by the antenna design of the IWR1443BOOST EVM. The design used in the IWR1443BOOST enables a wide FOV with elevation information for 3D point cloud information.
Frame rate	5 Hz	This parameter defines the data output and visualizer update rate.
Maximum range	10 m	The maximum range is defined by the radar chirp characteristics, and can be configured to suit application requirements. The maximum range defined for this reference design is with respect to the dimensions of the testing site.
Range resolution	4.7 cm	Range resolution is the ability of a radar system to distinguish between two or more targets on the same bearing but at different ranges.
Maximum velocity	2.05 m/s	This is the native maximum velocity obtained using a two-dimensional FFT on the frame data.
Velocity resolution	0.26 m/s	This parameter represents the capability of the radar sensor to distinguish between two or more objects at the same range that are moving with different velocities.

2 System Overview

2.1 Block Diagram

The TIDEP-01003 is implemented on the IWR1443BOOST EVM. The EVM is connected to a host PC through universal asynchronous receiver-transmitter (UART) for visualization.

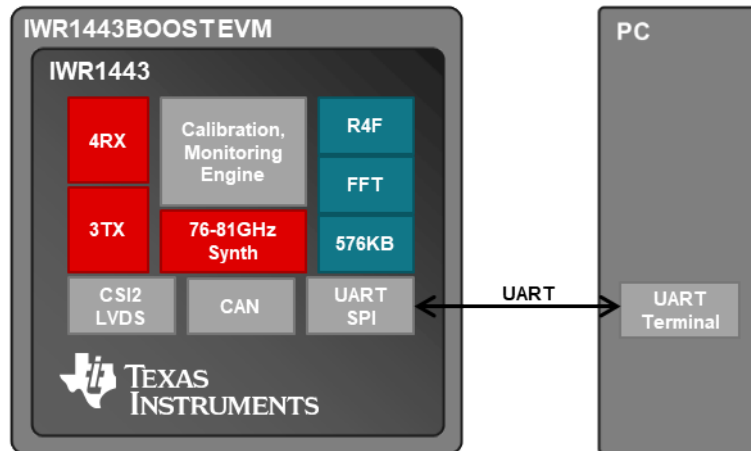


图 1. Zone Occupancy Detection System Block Diagram

2.2 Highlighted Products

2.2.1 IWR1443

The IWR1443 is a highly-integrated, single-chip radar device for industrial applications in TI's 45-nm, low-power RFCMOS technology, which is a FCBGA, 0.65-mm pitch package.

The radar subsystem (BSS) is responsible for the RF and analog functionality of the device. The subsystem incorporates a built-in self-test (BIST) processor for the continuous motoring and calibration of the analog and RF modules.

The master subsystem (MSS) contains a user-programmable ARM core, user-accessible memories, and peripherals for the configuration and control of the entire device. The MSS communicates with the BSS through the mmWave link API and the mailbox peripheral.

2.3 System Design Theory

2.3.1 Operation

The IWR1443 is loaded with a flashed image that, when booted and initialized, receives a chirp configuration specified using the zone occupancy visualizer. In the zone occupancy visualizer, the location and dimension of the zones to monitor are set as well as other visualization properties. Then, using the visualizer, the chirp configuration is loaded and sent to the sensor to start monitoring the area of interest for zone occupancy.

The strongest reflections reported by the radar device are reported as detected objects to the host PC through the UART. The detected objects collectively form a point cloud representation of the scene as seen by the sensor. If an object generates a point cloud of at least 3 points within a zone, the zone is considered occupied and the visualizer updates to highlight the occupied zone.

2.3.2 Use Case Considerations

This reference design is intended to demonstrate the detection of people or objects moving into a zone for an indoor environment. Given this use case, the system implements static clutter removal so that other permanent fixtures in the scene, such as walls, do not trigger a zone occupancy detection. The use case drove the design of the chirp configuration in 表 2 with primary considerations being achieving high range resolution and sufficient maximum velocity for human movement, including walking.

表 2. Chirp Configuration

KEY INPUT PARAMETERS	
PERFORMANCE PARAMETERS	
Antenna pattern	Two Tx, four Rx in azimuth plane
Maximum range	10.125 m
Range resolution	4.7 cm
Maximum velocity	2.05 m/s
Velocity resolution	0.26 m/s
Frame duration	200 ms
ADC sampling rate	7.5 MSPS
DERIVED CHIRP DESIGN PARAMETERS	
Chirp valid sweep bandwidth	3.2 GHz
Chirp repetition time	129.7 μ s
Number of samples per chirp	240
Nfft_range	256
Number of chirps per frame	48
Nfft_doppler	16

3 Hardware, Software, Testing Requirements, and Test Results

3.1 Required Hardware and Software

3.1.1 Hardware

The following hardware is required to get the demonstration running:

- [IWR1443 EVM](#)
- A 5-V, 2.5-A power supply for the IWR1443 EVM
- A PC for Code Composer Studio™ (CCS) and the demonstration UART terminal

3.1.2 Software

For this reference design, software is provided for the IWR1443 device and the host PC.

The software required for the target IWR1443:

- [Latest mmWave SDK](#). The SDK automatically installs the required component versions. These components are listed in the SDK's release notes in the /docs folder of the software package. Install the SDK and all required components before installing and building the demonstration source.
- [Code Composer Studio \(CCS\)](#). See the SDK release notes for the required version.
- [Latest mmWave Industrial Toolbox](#). Using CCS, access and install the mmWave Industrial Toolbox through the Resource Explorer. The Industrial Toolbox contains a quick start guide with precompiled binaries for the device, the source code, and a detailed user's guide to run the demo as presented in this reference design. When installed, the material specific to the zone occupancy detection system is located at [mmWave Industrial Toolbox install directory]/labs/lab0016_zone_occ_14xx.

The software required for the host PC:

- [Latest mmWave Industrial Toolbox](#). The zone occupancy detection visualizer is packaged in the Industrial Toolbox. The /gui folder includes the compiled executable and source code for the visualizer.

The application software used in this reference design is from the mmWave SDK version 1.02.00.05 and mmWave Industrial Toolbox version 2.5.0. TI recommends getting the latest version of the demo software from the mmWave Industrial Toolbox.

3.2 Testing and Results

3.2.1 Test Setup

To characterize and demonstrate the capabilities of the zone occupancy detection system, the IWR1443Boost EVM was set up in a conference room as depicted in 图 2.

The setup conditions were as follows:

- EVM positioning: The EVM was mounted at a height of 1.5 m above the ground. The EVM was oriented vertically with the antenna facing straight ahead to survey the area of interest.
- Ground truth reference: Marker cones were placed on the ground to define a ground truth reference grid. The grid was defined by range and angle from 0 m to 11 m and 0 to 180 degrees (where possible and not limited by room dimensions). Each grid of zone sectors had a height of 1 m and spanned a 30 degree angle.

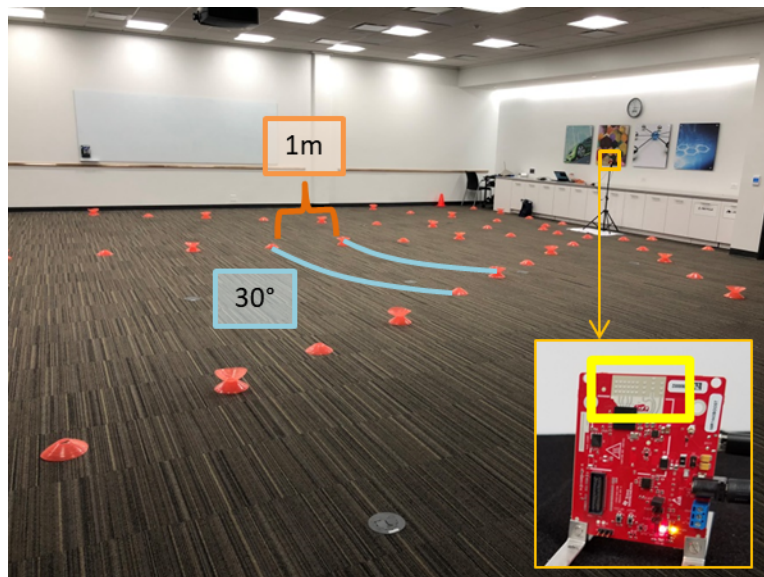


图 2. Zone Occupancy Detection Testing Environment and Configuration

The areas of zone detection were characterized for two test cases:

- Human walking in an arc from 0 to 180 degrees at a constant range.
- Human walking in a straight line at a constant angle

图 3 和 图 4 illustrate the paths the person walked for the arc test and straight line tests. For each path indicated by a red line, the person walked the path once and then back, effectively traversing the path twice. The black dotted lines indicate the walls of the room that limited the range of the testing. For each path walked, the output of the zone occupancy system was recorded and the cumulative point cloud results were saved.

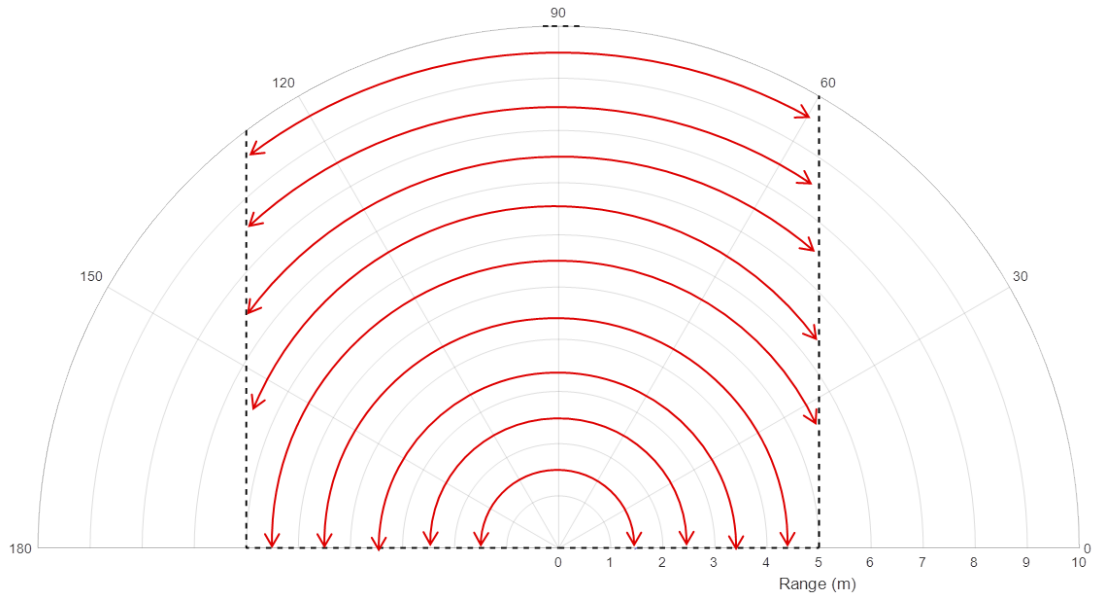


图 3. Human Walking Paths in an Arc Test Case

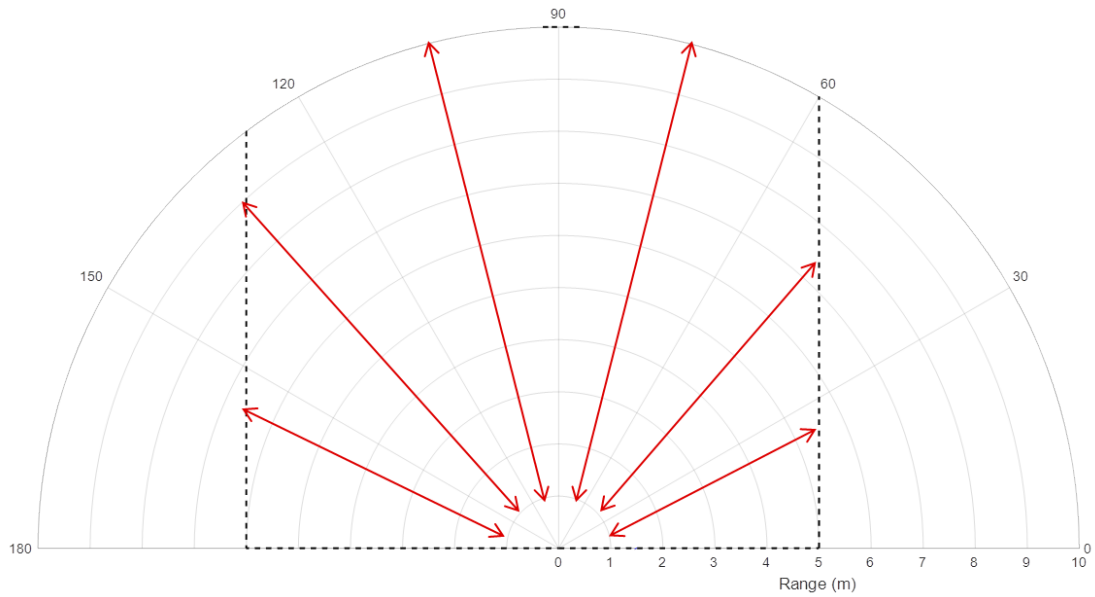


图 4. Human Walking Paths in a Straight Line Test Case

3.2.2 Test Results

3.2.2.1 Test Case: Human Walking in an Arc From 0 to 180 Degrees at a Constant Range

The zone occupancy detection system implements an occupancy detection rule that requires at least 3 simultaneously detected points for a zone sector to be considered occupied. As described above, the arc walking test case had 9 test paths; for each one, the output of the zone occupancy detection system was captured during each path walk.

图 5 shows a series of snapshots from one of the arc test paths and illustrates how the zone occupancy detection system responded. In the top left and bottom right panels, the human has walked outside the sensor's field of view (0-30° and 150-180°), resulting in no detections. From the 2nd to 5th panel, the person is walking through the angles 30-60°, 60-90°, 90-120°, and then 120-150°. In these zones within the sensor field of view, the person walking generated a detectable point cloud, which triggered the zone occupancy system to highlight the grid sector to illustrate occupancy.

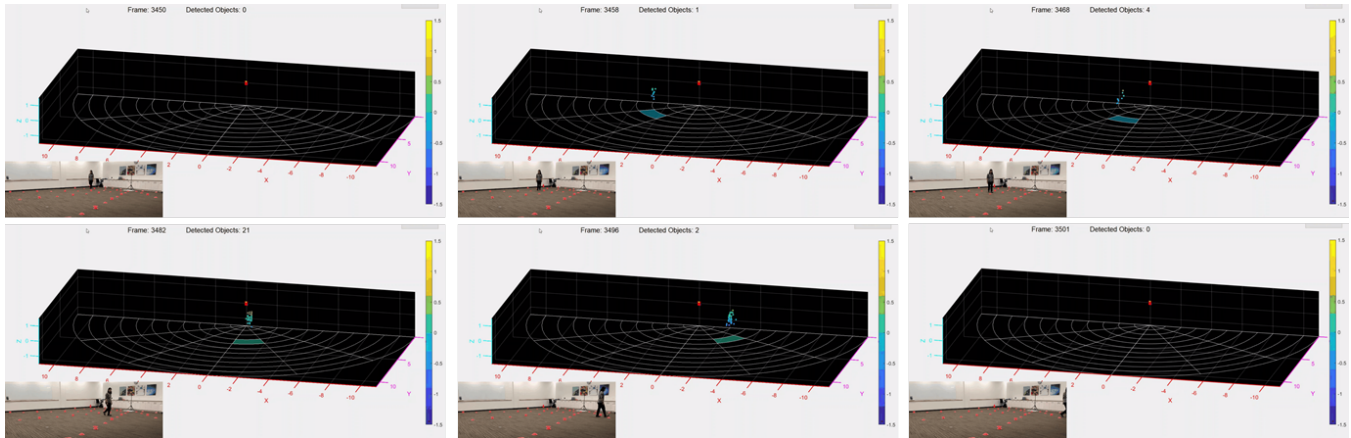


图 5. Snapshots of Arc Test: Walking From 0-180° at 3 to 4m Range

The results of the arc walking test case are compiled and represented in 图 6. The figure was generated by plotting the saved point cloud data from each test path together onto the single plot. Each color represents a different test path. Each circle is a point in the cumulative point cloud for the path walked. For example, the dark purple circles represent the total recording of the point cloud as the person walked in an arc from 180 degrees to 0 degrees and then back to 180 degrees at a distance of 1 to 2 m from the radar.

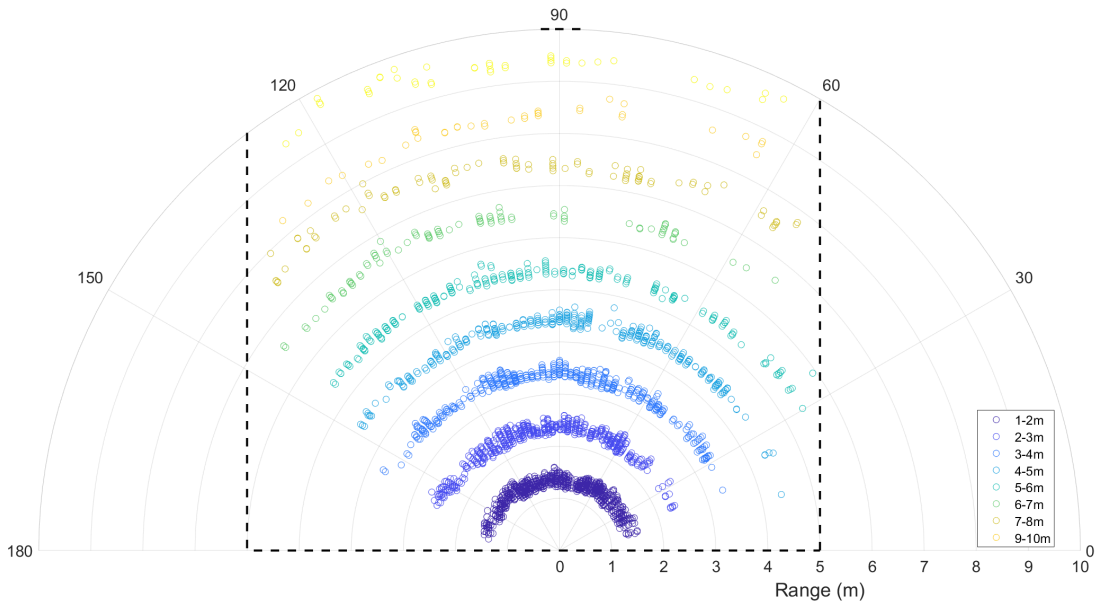


图 6. Cumulative Point Cloud Results From Human Walking in an Arc Test Case

表 3 summarizes the ability of the zone occupancy detection system to detect a person walking the arc paths described in 图 3. In some cases, such as 0-30 degrees at 3 to 4 m, the cumulative point cloud plot shows detections in that sector but the table denotes that the zone occupancy detection system was not triggered. At these angle and range combinations, the person did not generate at least 3 points in a single frame as the person walked across the zone sector.

表 3. Zone Occupancy Detection Summary for Arc Test

		Angle (°)					
		0-30	30-60	60-90	90-120	120-150	150-180
Range (m) ⁽¹⁾	1-2	✓	✓	✓	✓	✓	✓
	2-3	X	✓	✓	✓	✓	✓
	3-4	X	✓	✓	✓	✓	X
	5-6	X	✓	✓	✓	✓	X
	6-7	-	✓	✓	✓	✓	X
	7-8	-	✓	✓	✓	✓	-
	8-9	-	X	✓	✓	X	-
	9-10	-	X	✓	✓	X	-

⁽¹⁾ Legend: ✓ = Zone occupancy detection triggered, X = No detection triggered, - = Wall obstruction, not testable

3.2.2.2 Test Case: Human Walking in a Straight Line at a Constant Angle

图 7 shows a series of snapshots from one of the straight line test paths, and illustrates how the zone occupancy detection system responded. In the top left, the human starts walking at 1 to 2 m, and as the snapshots progress, ends at 9 to 10 m. In these zones, the person walking generated a detectable point cloud, which triggered the zone occupancy system and highlighted the zone sector to illustrate occupancy.

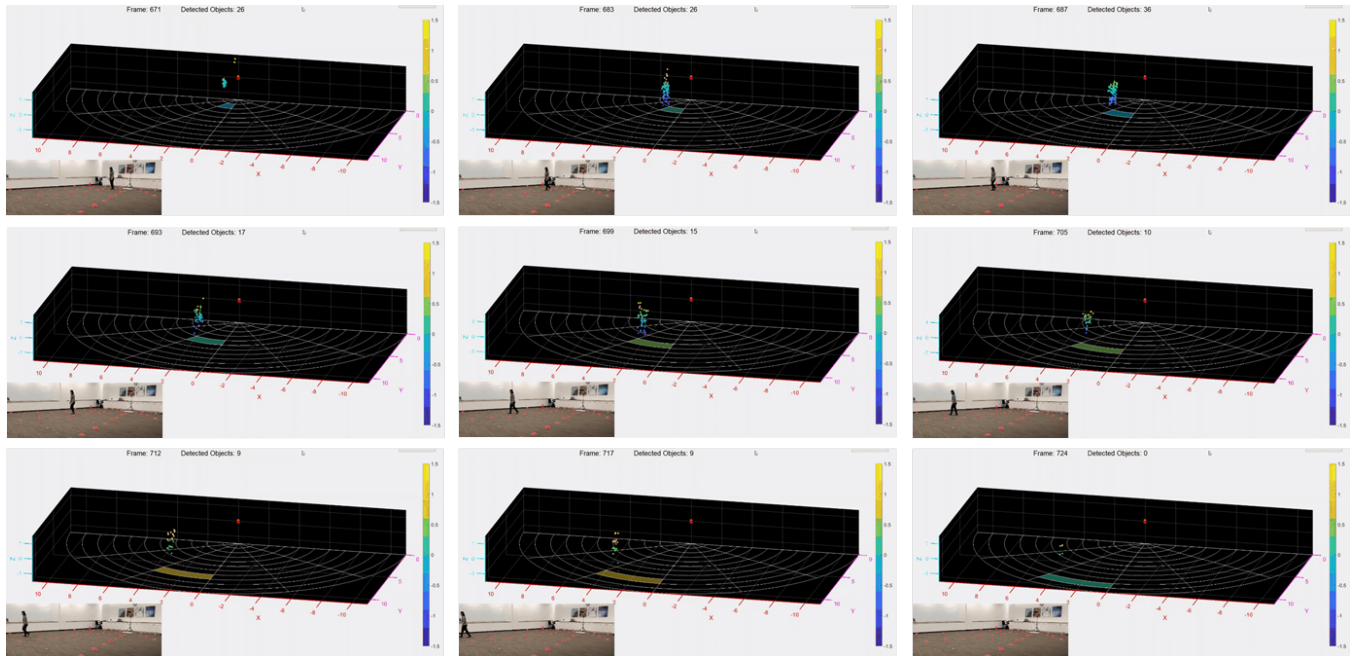


图 7. Snapshots of Straight Line Test: Walking From 1 to 10 m at 60 to 90° Angle

The compiled results of the straight line walking test case are depicted in 图 8. Each color represents a different test path, and each circle is a point in the cumulative point cloud for the path walked. For example, the green circles represent the total recording of the point cloud as the person walked a line from 1 m to 10 m and back to 1 m at a constant angle within 90 to 120 degrees.

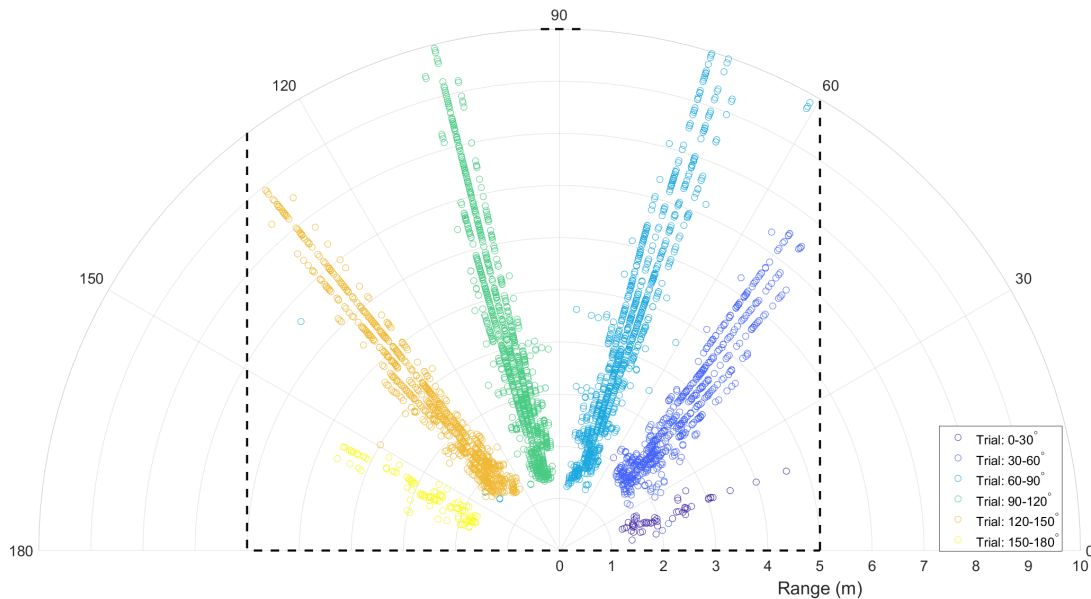


图 8. Cumulative Point Cloud Results From Human Walking in a Straight Line Test Case

表 4 summarizes the zone occupancy detection system capabilities for detecting a person walking the straight line paths described by 图 4.

表 4. Zone Occupancy Detection Summary for Straight Line Test

		Range (m)								
		1-2	2-3	3-4	4-5	5-6	6-7	7-8	8-9	9-10
Angle (°) ⁽¹⁾	0-30	✓	✓	X	X	X	-	-	-	-
	30-60	✓	✓	✓	✓	✓	✓	✓	X	-
	60-90	✓	✓	✓	✓	✓	✓	✓	✓	✓
	90-120	✓	✓	✓	✓	✓	✓	✓	✓	✓
	120-150	✓	✓	✓	✓	✓	✓	✓	✓	X
	150-180	✓	✓	X	X	X	X	-	-	-

⁽¹⁾ Legend: ✓ = Zone occupancy detection triggered, X = No detection triggered, - = Wall obstruction, not testable

3.2.3 Observations and Conclusions From Test Results

The results of the arc and straight line walking test cases demonstrate the capabilities of the zone occupancy detection system. Using the IWR1443Boost EVM, the system demonstrated the ability to detect the zone a human was walking in for a range up to 10 m and over a 120° field of view. Furthermore, with three transmitters on the IWR1443, elevation information is enabled and 3D point clouds are generated. As shown in 图 7 when the person is closer to the sensor, a rich and dense point cloud with elevation information representative of the sensed object's height is generated.

The zone occupancy detection system supports the configuration and customization for specific use cases. The size of the grids that define each zone are fully configurable by range and angle bin size. The detection range can be extended or reduced by designing and loading a different chirp configuration. The [mmWave Sensing Estimator](#) tool can be used to design a chirp configuration based on an application's sensing requirements.

4 Design Files

4.1 Schematics

To download the schematics, see the design files at <http://www.ti.com/tool/TIDEP-01003>.

4.2 Bill of Materials

To download the bill of materials (BOM), see the design files at <http://www.ti.com/tool/TIDEP-01003>.

4.3 Altium Project

To download the Altium Designer® project files, see the design files at <http://www.ti.com/tool/TIDEP-01003>.

4.4 Gerber Files

To download the Gerber files, see the design files at <http://www.ti.com/tool/TIDEP-01003>.

4.5 Assembly Drawings

To download the assembly drawings, see the design files at <http://www.ti.com/tool/TIDEP-01003>.

5 Software Files

To download the software files, see the design files at <http://www.ti.com/tool/TIDEP-01003>.

6 Related Documentation

1. Texas Instruments, [IWR1443 Data Sheet](#)
2. Texas Instruments, [IWR1443 Evaluation Module \(IWR1443BOOST\) Single-Chip mmWave Sensing Solution](#), user's guide
3. Texas Instruments, [IWR16xx/14xx Industrial Radar Family](#), technical reference manual
4. Texas Instruments, [mmWave SDK](#), tools folder

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