

# A NEW ARRAY GEOMETRY FOR DOA ESTIMATION WITH ENHANCED DEGREES OF FREEDOM

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### Abstract

This work presents a new array geometry, which is capable of providing  $O(M^2N^2)$  DOF using only MN physical sensors via utilizing the second-order statistics of the received data. This new array is composed of multiple, identical minimum redundancy subarrays, whose positions follow a minimum redundancy configuration. Thus the new array is a minimum redundancy array (MRA) of MRA subarrays, and is termed nested MRA (NMRA). The sensor positions, aperture length, and the number of DOF of the new array can be predicted if these parameters of

## **Numerical Examples**

#### **Simulation 1**

**Comparison of DOF, Aperture for different array geometries** versus total number of sensors





Shanghai, China

MRA subarrays are given.

**Keywords:** Sensor arrays, minimum redundancy array (MRA), **DOA estimation, co-array, nested array.** 



Fig. 1 Geometry of NMRA with 3 identical 4-element minimum redundancy subarrays

**Construction of NMRA:** 

**Properties of NMRA:**  $\succ$  Location Set:  $\mathbb{D}_V = \mathbb{D}_B \oplus \mathbb{D}_A$ 

Fig. 2 DOF comparison

#### **Advantage 1**

✓ The proposed NMRA can provide more DOF, larger aperture than Nested Array and Coprime Array ✓ The superiority becomes more and more obvious with increase of total number of sensors

#### **Simulation 2**

**DOA estimation comparison of 12 physical sensors,** For NMRA, M=3, N=4



The NMRA can resolve all the 37

47

1000

Subarray A:  $\mathbf{u}_M = [m_1 \ m_2 \cdots m_N] \ d,$ Subarray B:  $\mathbf{u}_N = [n_1 \ n_2 \cdots n_N] \ D,$ •NMRA :  $\mathbf{v} = \mathbf{u}_N \oplus \mathbf{u}_M.$  $\oplus$  : cross summation

Aperture:  $l_V \cdot d = (l_A + l_B \cdot f_A)d$ > DOF:  $f_V = f_A \cdot f_B$ **Signal Model:**  $\mathbf{x}(t) = \mathbf{A}\mathbf{s}(t) + \mathbf{n}(t)$ s(t): source signals vector (Unknown) Q sources, K-elements array

### **Procedure of DOA Estimation**

Vectorizing  $R_{XX}$  can get a  $K^{2}*1$  vector z  $\mathbf{z} = \operatorname{vec}(\mathbf{R}_{\mathbf{X}\mathbf{X}}) = \operatorname{vec}\left|\sum_{n=1}^{\infty} \sigma_{q}^{2} \mathbf{a}(\theta_{q}) \mathbf{a}^{H}(\theta_{q})\right| + \sigma_{n}^{2} \vec{\mathbf{1}}_{n} = \mathbf{B}\mathbf{c} + \sigma_{n}^{2} \vec{\mathbf{1}}_{n}$ **Estimation of**  $\mathbf{B} = [\mathbf{a}^*(\theta_1) \otimes \mathbf{a}(\theta_1) \dots \mathbf{a}^*(\theta_0) \otimes \mathbf{a}(\theta_0)]$ covariance matrix  $\mathbf{c} = \begin{bmatrix} \sigma_1^2 & \sigma_2^2 \cdots \sigma_Q^2 \end{bmatrix}^T$ ;  $\otimes$ : is Kronecker product unique elements (lags) of virtual array  $\mathbf{z}_1 = \text{unique}(\mathbf{z}) = \mathbf{B}_1 \mathbf{c} + \sigma_n^2 \vec{\mathbf{1}}_n$ **Difference Co-array** 

Fig. 5 RMSE versus SNR

**Fig.6 RMSE versus Snapshot** 





### **The DOF of NMRA**

Subarray A and Subarray B are both MRAs and their numbers of DOF can be expressed as  $f_A$  and  $f_B$ , then

 $f_V = f_A \cdot f_B$  $= (M^{2} - M + 1 - M_{R})(N^{2} - N + 1 - N_{R}) \propto (M^{2}N^{2})$ 

✓ NMRA can provide  $O(M^2 N^2)$  DOF using only MN physical sensors.

### Advantage 2

✓ The NMRA has better DOA estimation performance than the NA and CACIS.



- Proposed a new array geometry, NMRA, which can be easily constructed.
- NMRA has a larger aperture as well as a higher number of **DOF** than the nested array and the CACIS.
- It can resolve more sources than sensors.
- It has a better DOA estimation performance than the NA and CACIS.