

Contents

1. INTRODUCTION TO RADAR	1-24
1.1. Introduction	1
1.2. Radar Block Diagram	2
1.3. Determination of Co-ordinates in Radar	4
1.3.1. Range	5
1.3.2. Bearing	7
1.3.3. Altitude	8
1.4. Target Resolution	8
1.4.1. Range Resolution	8
1.4.2. Bearing Resolution	9
1.5. Applications of Radar	9
1.6. Radar Frequencies	10
1.7. Radar Development	12
1.8. Different Types of Radar	15
1.9. Basic Pulse Radar System	17
■ Summary	21
■ Review Questions	23
2. THE RADAR EQUATION	25-54
2.1. Introduction	25
2.2. Simple Form of Radar Equation	25
2.3. Prediction of Range Performance	27
2.3.1. Radar Performance	27
2.4. Minimum Detectable Signal	32
2.4.1. Threshold Detection	32
2.5. Radar Receiver Noise and Signal-to-Noise Ratio	33
2.6. System Losses	35
2.6.1. Plumbing Loss	35
2.7. Integration of Radar Pulses	35
2.8. Radar Cross-Section of Targets	40
2.9. Statistical Description of RCS	42
2.10. RCS Fluctuations of Targets	43
2.11. Target Fluctuation Models	44
2.12. Swerling Models	45
2.13. Antenna Parameters	46
2.13.1. Directivity or Directive Gain	47
2.13.2. Power Gain	48
2.13.3. Effective Aperture or Total Scattering Cross Section	48
2.13.4. Wave Polarization	49

2.13.5. Major and Side (Minor) Lobes	51
2.13.6. Front-to-Back Ratio	52
2.13.7. Beam Efficiency	52
■ Summary	53
■ Review Questions	54
3. MTI AND PULSE DOPPLER RADAR	55–82
3.1. Introduction	55
3.2. Moving Target Indicator Radar	55
3.2.1. A Simple Block Diagram of MTI Radar	56
3.2.2. MTI Radar Using Power Oscillator as Transmitter	58
3.3. Delay Lines and Cancellers	58
3.3.1. Delay Lines	59
3.4. Staggered Pulse Repetition Frequencies	65
3.4.1. Sub Clutter Visibility	66
3.4.2. The Cancellation Ratio	66
3.4.3. The Target Visibility Factor	66
3.5. Range Gated Doppler Filters	67
3.6. Digital MTI Signal Processing	68
3.7. Non-Coherent MTI	69
3.8. Pulse Doppler Radar	69
3.9. MTI From Moving Platform (AMTI)	70
3.9.1. Coherent AMTI	71
3.9.2. Pulse Doppler AMTI	72
3.9.3. Non-Coherent AMTI	72
3.9.4. Fluctuation Caused by Platform Motion	72
3.9.5. Effects of Side Lobes on Pulse Doppler AMTI Radar	72
3.10. Limitations to MTI Performance	73
3.10.1. Equipment Instabilities	73
3.10.2. Internal Fluctuation of Clutter	73
3.10.3. Antenna Scanning Modulation	74
3.10.4. Limiting in MTI Radar	74
3.10.5. Envelope Processing in MTI Radar	74
3.11. Moving Target Detector (MTD)	75
■ Summary	80
■ Review Questions	81
4. TRACKING RADAR	83–117
4.1. Introduction	83
4.2. Tracking With Radar	83
4.2.1. Radar Servo Tracking System	83
4.2.2. Types of Tracking Radar	84
4.3. Block Diagram of Tracking Radar	85
4.4. Sequential Lobbing	86
4.5. Conical Scanning	87
4.6. Mono Pulse Tracking	88
4.6.1. Amplitude Comparison Mono Pulse	89
4.6.2. Phase Comparison Mono Pulse Tracking	90

4.7.	Target Acquisition and Tracking in Range	91
4.7.1.	Target Acquisition	91
4.7.2.	Range Tracking	93
4.8.	Low Angle Tracking	96
4.9.	Servo Systems For Tracking Radar	100
4.10.	Limitations to Tracking Accuracy	103
4.11.	Error Reduction Techniques	107
4.11.1.	Multipath-Error Reduction	107
4.11.2.	Target Angle and Range Scintillation (Glint) Reduction	108
4.11.3.	Reduction of Internally Caused Errors	108
4.11.4.	nth-Time-Around Tracking	108
4.12.	Mirror-Scanned Antenna (Inverse Cassegrain)	109
4.13.	On-Axis Tracking	109
4.14.	Comparisons of Tracking Radar	110
4.15.	Tracking with Surveillance Radar	111
■	Summary	114
■	Review Questions	116
5.	DETECTION OF SIGNALS IN NOISE	118–139
5.1.	Introduction	118
5.2.	Matched Filter Receiver	118
5.3.	Effect of S/N Ratio Over the Detection of Weak Signal	120
5.4.	Correlation Detection	121
5.5.	Threshold Detection Criteria	122
5.6.	Radar Detection as Hypothesis Testing	122
5.7.	Detection Theory	125
5.7.1.	Neyman Pearson Observer	125
5.7.2.	Ideal Observer	125
5.7.3.	Sequential Observer	125
5.7.4.	Likelihood Ratio	126
5.8.	Detector Characteristics	126
5.8.1.	The Envelope Detector : Non-Coherent Detector	127
5.8.2.	Logarithmic Detector	127
5.8.3.	Zero Crossing Detectors	127
5.8.4.	Coherent Detector	128
5.8.5.	Synchronous Detection using Phase Locked Loop	129
5.8.6.	I & Q Demodulator	129
5.9.	Detection of Non-Fluctuating Target in Noise	130
5.10.	Binary and Commulative Integration : Non-fluctuating Target	132
5.11.	Albersheim's Equation	132
5.12.	Shnidman's Equation	133
5.13.	Automatic Detection	134

5.14. Constant False Alarm Rate (CFAR)	135
5.15. Cell Averaging CFAR	135
■ Summary	135
■ Review Questions	138
6. INFORMATION FROM RADAR SIGNALS	140–179
6.1. Basic Radar Measurements	140
6.2. Measurements of Phase and Amplitude	141
6.2.1. Phase Derivatives	141
6.2.2. Amplitude Derivatives	142
6.2.3. The Six Measurement Derivatives	142
6.3. Review of Radar Measurements	143
6.4. Theoretical Accuracy of Radar Measurements	145
6.5. Amplitude, Phase and Frequency of a Sine Wave	146
6.6. Range Accuracy (Leading edge Measurement)	147
6.7. Time-delay Accuracy and Effective BW	149
6.8. Accuracy of Frequency (or Doppler Velocity) Measurement	151
6.9. Ambiguity Diagram	155
6.9.1. Ambiguity Function of Simple Matched Pulse	156
6.10. Pulse Compression	158
6.10.1. Concept of Operation	159
6.10.2. Analog Pulse Compression	161
6.10.3. Digital Pulse Compression	162
6.11. Target Recognition	168
6.11.1. Automatic Target Detection and Recognition Overview	170
6.12. Clutters	173
6.12.1. Introduction	173
6.12.2. Types of Radar Clutter	173
6.12.3. Clutter Reduction	176
6.12.4. Angels	177
■ Summary	177
■ Review Questions	179
APPENDICES	181–239
Appendix A : Glossary	183–201
Appendix B : Decibel (dB)	202–207
Appendix C : Abbreviations and Acronyms	208–239
INDEX	240–242