FMCW LIDAR Range and Velocity Estimation Beyond the Laser Coherence

Martin Peyrou, Yannis Le Guennec, Sylvie Menezo

FMCW LIDAR RANGE AND VELOCITY ESTIMATION BEYOND THE LASER COHERENCE

Martin Peyrou[1], **Yannis Le Guennec**[2], **Sylvie Menezo**[1]

[1] *Scintil Photonics, 7 Parvis Louis Néel, 38040 Grenoble, France*
[2] *Université Grenoble Alpes, CNRS, Grenoble INP, GIPSA-Lab, 11 Rue des Mathématiques, 38400 Saint-Martin-d'Hères, France*

martin.peyrou@scintil-photonics.com

ABSTRACT

Frequency modulated continuous wave (FMCW) LIDAR is a promising technology for high precision 3D sensing applications. However, due to laser phase noise, these systems are usually restricted to target detection below 100 m. In this paper, we present a digital signal processing technique to extend the target range and velocity estimations beyond the laser coherence length. This technique is tested over realistic data from a Monte Carlo model.

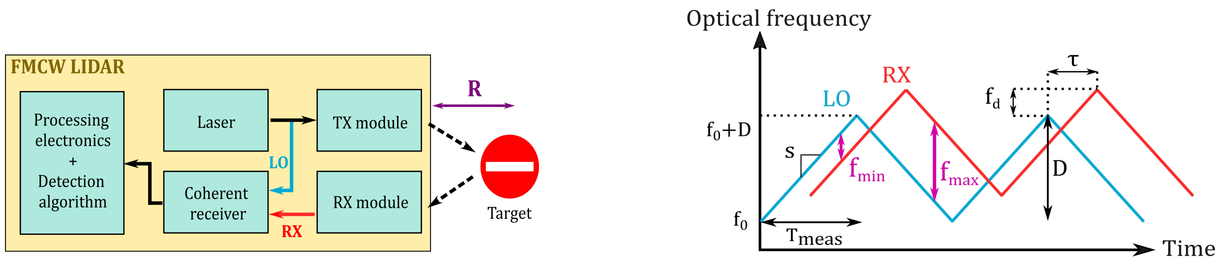
MOTS-CLEFS : *LIDAR; laser linewidth; estimation; precision*

1. INTRODUCTION

High precision 3D sensing systems as Frequency Modulated Continuous Wave (FMCW) LIDARS are gaining interest for automotive, robotic and medical applications. FMCW LIDAR is based on coherent detection and shows high resolution and instantaneous radial velocity information [1]. However, the laser phase noise strongly impacts the received signal spectrum, which spreads from a narrow squared Cardinal Sine to a Lorentzian function for targets beyond the laser coherence length, L_c, making it uncertain the range and velocity estimations. Embedded digital signal processing (DSP) is a promising approach to extend LIDAR detection range beyond L_c [2]. In this article, we further evaluate the Least Square Estimation (LSE)-based algorithm suitability for the estimation of velocity beyond L_c.

2. FMCW LIDAR PRINCIPLE

The considered FMCW LIDAR is presented on Fig. 1a. The laser optical frequency is modulated with a triangular waveform Fig. 1b to enable target range and velocity estimation. During the measurement period T_{meas}, the laser frequency is chirped with a slope $s = D/T_{meas}$, where D is the frequency excursion. The FMCW signal hits a target and is backscattered to the coherent receiver (RX module) with a delay τ where it mixes with the reference local oscillator (LO).



(a) (b)

Figure 1: (a) FMCW LIDAR system. (b) FMCW transmitted (blue) and reflected (red) waveforms

Target range, R and velocity, V are retrieved from the minimum, f_{min} and maximum, f_{max} detected beat frequencies, which are estimated after Fourier Transform (FT) of the photodetected signal, as:

$$R = \frac{c}{4s}(f_{max} + f_{min}) \quad \text{and} \quad V = \frac{\lambda}{4}(f_{max} - f_{min}) \tag{1}$$

where c is the light velocity in vacuum and λ is the laser wavelength.

3. Range and Velocity Estimation beyond the Laser Coherence Length

The laser phase noise is modeled as a flat frequency noise with power spectrum density $S_{v_n}(f)$ depending on the laser linewidth Δv (2). Frequency noise samples are integrated in time to express laser phase noise contributions Φ_n of the direct and reflected paths into the photodetected beat current, I_b with beat frequency f_b=f_{min} or f_{max} as expressed in (2). The periodogram (PER) of I_b is evaluated over T_{meas}. An LSE algorithm is used to search the expected Lorentzian shape over the PER of I_b and estimates f_{min} and f_{max} to derive R and V (1). Tab. 1 details the system specifications, where the target is located beyond L_c.

$$S_{v_n}(f) = \frac{\Delta v}{2\pi} \quad , \quad \Phi_n = \int_t 2\pi\Delta v dt \quad \text{and} \quad I_b = cos(2\pi f_b t + \Phi_n(t) - \Phi_n(t-\tau)) \tag{2}$$

Parameter	Value
LIDAR output power	10 mW
Laser linewidth	1 MHz
Measurement time T_{meas}	10 μs
Frequency excursion D	1 GHz
Attenuation coeff in air α	0.43 dB/km
Target range R	150 m
Target velocity V	60 km/h
Target reflectivity	10%
Receiver aperture size	1 cm^2
Detector responsivity	0.8 A/W
Detector bandwidth	500 MHz
Estimation algorithm	LLSE

Table 1: System specifications

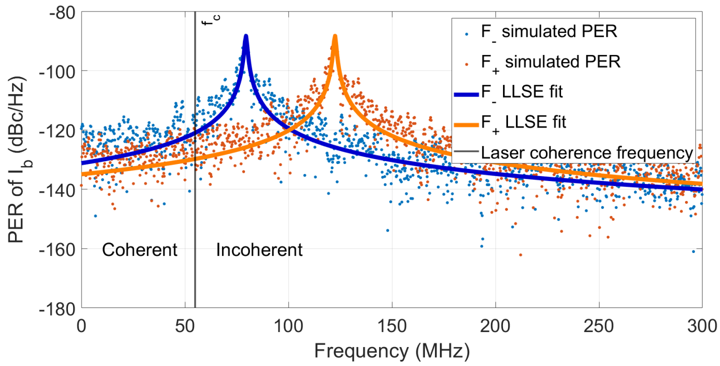


Figure 2: Periodogram of the photocurrent with LLSE fitting

4. Simulation Results and Discussion

As it can be seen from Fig. 2, the Lorentzian LSE (LLSE) algorithm accurately fits the simulated PSDs for a target located at 150 m, i.e. beyond the laser coherent length L_c = 82 m (corresponding to the detected "coherence frequency" f_c=55 MHz on Fig. 2). From LLSE, estimated f_- and f_+ are 78.7665 MHz and 121.775 MHz respectively, which corresponds to a target range and velocity of 150.406 m and 59.997 km/h respectively. These results are in good agreement with the expected values of 150 m and 60 km/h (Tab. 1). However, for higher velocity targets, f_- approaches zero, making it difficult LLSE fitting.

Conclusion

In this paper, a LSE-based digital signal processing technique is used for target range and velocity estimations beyond the laser coherence length. A Monte Carlo model for the FMCW LIDAR, including the laser phase noise, is introduced to provide realistic data to test the proposed signal processing technique. First simulation results confirm that the target range and velocity are accurately estimated for a target distance larger than L_c. LSE can be applied to any laser lineshape, providing that it is known for LSE detection. Future work will be conducted to evaluate the accuracy of LSE-based range and velocity estimations, considering a wide set of scenarios.

References

[1] B. Behroozpour, P. A. M. Sandborn, M. C. Wu and B. E. Boser, "Lidar System Architectures and Circuits," *IEEE Communications Magazine*, pp. 135-142, 2017.

[2] T. Kim, P. Bhargava and V. Stojanovic, "Optimal Spectral Estimation and System Trade-Off in Long-Distance Frequency-Modulated Continuous-Wave Lidar," *2018 ICASSP*, pp. 1583-1587, 2018.