Week (6)
Signal-Space Analysis

5.3 Conversion of the Continuous AWGN Channel into a Vector Channel

5.5 Coherent Detection of Signals in Noise: Maximum Likelihood Decoding

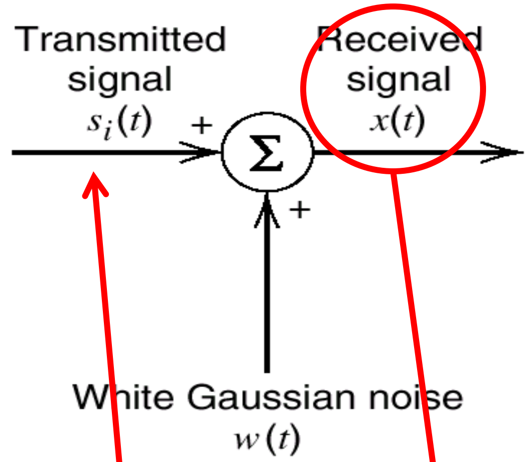


Figure 5.2 Additive white Gaussian noise (AWGN) model of a channel.

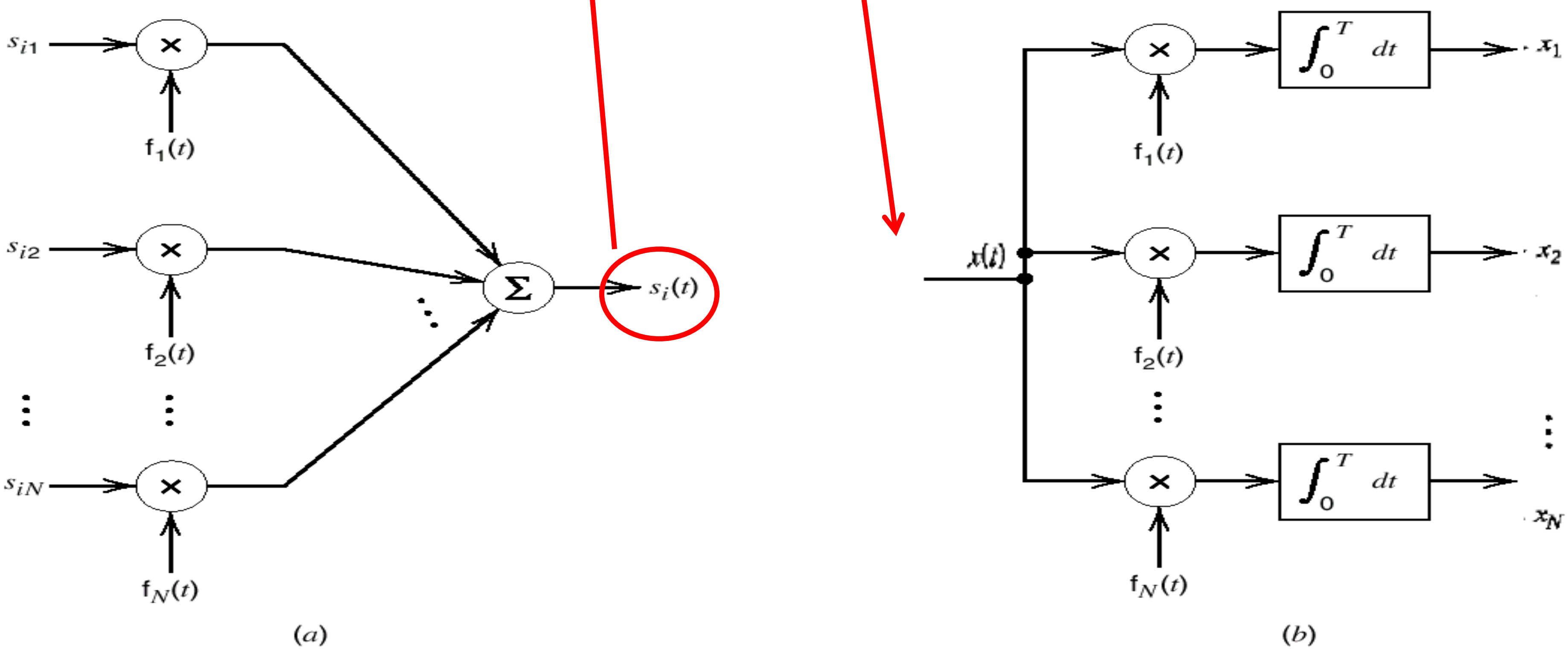


Figure 5.3 ***(a) Synthesizer for generating the signal $s_i(t)$.***
(b) Analyzer for generating the set of signal vectors $\{s_i\}$.

5.3 Conversion of the Continuous AWGN Channel into a Vector Channel

Suppose that the input to the bank of N product integrators or correlators in Figure 5.3b is not the transmitted signal $s_i(t)$ but rather the received signal $x(t)$ defined in accordance with the idealized AWGN channel of Figure 5.2. That is to say,

$$x(t) = s_i(t) + w(t), \qquad \begin{cases} 0 \leq t \leq T \\ i = 1, 2, \ldots, M \end{cases} \tag{5.28}$$

where $w(t)$ is a sample function of a white Gaussian noise process $W(t)$ of zero mean and power spectral density $N_0/2$. Correspondingly, we find that the output of correlator j, say, is the sample value of a random variable X_j, as shown by

$$\begin{aligned} x_j &= \int_0^T x(t)\phi_j(t)dt \\ &= s_{ij} + w_j, \qquad j = 1, 2, \ldots, N \end{aligned} \tag{5.29}$$

The first component, s_{ij}, is a deterministic quantity contributed by the transmitted signal $s_i(t)$; it is defined by

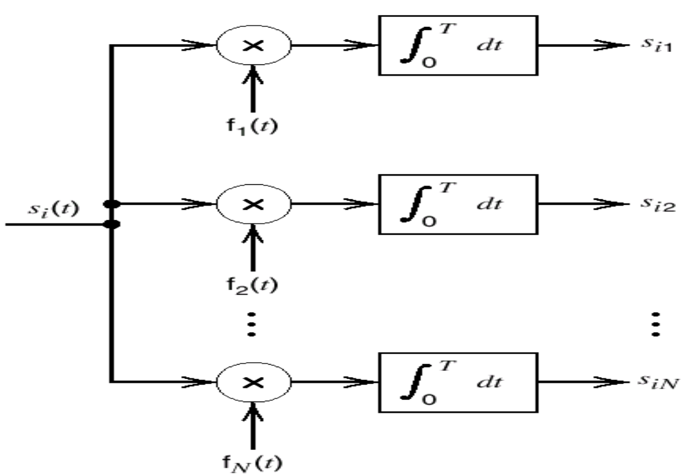
$$s_{ij} = \int_0^T s_i(t)\phi_j(t)dt \tag{5.30}$$

The second component, w_j, is the sample value of a random variable W_j that arises because of the presence of the channel noise $w(t)$; it is defined by

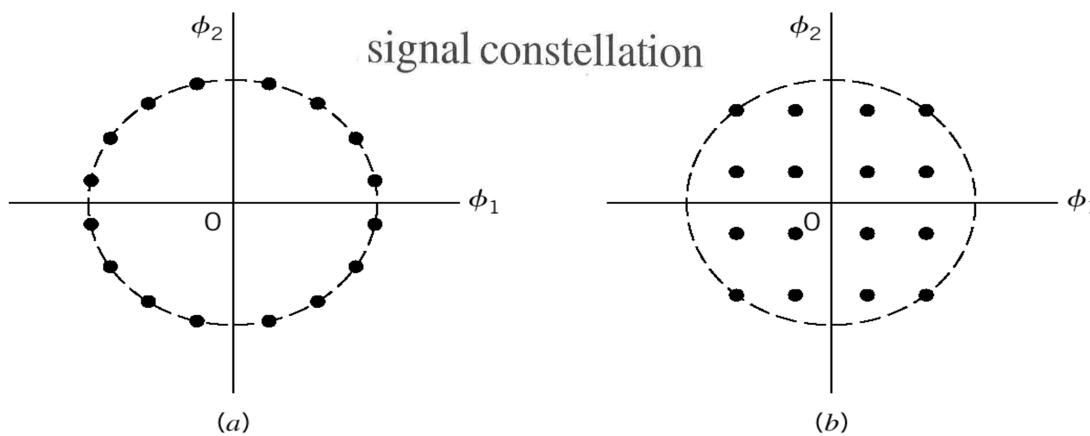
$$w_j = \int_0^T w(t)\phi_j(t)dt \tag{5.31}$$

5.5 Coherent Detection of Signals in Noise: Maximum Likelihood Decoding

Suppose that in each time slot of duration T seconds, one of the M possible signals $s_1(t)$, $s_2(t), \ldots, s_M(t)$ is transmitted with equal probability, $1/M$. For geometric signal representation, the signal $s_i(t)$, $i = 1, 2, \ldots, M$, is applied to a bank of correlators, with a common input and supplied with an appropriate set of N orthonormal basis functions. The resulting correlator outputs define the *signal vector* $\mathbf{s}_i$. Since knowledge of the signal vector $\mathbf{s}_i$ is as good as knowing the transmitted signal $s_i(t)$ itself, and vice versa, we may represent $s_i(t)$ by a point in a Euclidean space of dimension $N \le M$. We refer to this point as the *transmitted signal point* or *message point*. The set of message points corresponding to the set of transmitted signals $\{s_i(t)\}_{i=1}^{M}$ is called a *signal constellation*.



(b)



Signal constellation for (a) M-ary PSK and (b) corresponding M-ary QAM, for M = 16.

However, the representation of the received signal $x(t)$ is complicated by the presence of additive noise $w(t)$. We note that when the received signal $x(t)$ is applied to the bank of N correlators, the correlator outputs define the observation vector **x**. From Equation (5.48), the vector **x** differs from the signal vector $\mathbf{s}_i$ by the *noise vector* **w** whose orientation is completely random. The noise vector **w** is completely characterized by the noise $w(t)$;

Now, based on the observation vector **x**, we may represent the received signal $x(t)$ by a point in the same Euclidean space used to represent the transmitted signal. We refer to this second point as the *received signal point.* The received signal point wanders about the message point in a completely random fashion, in the sense that it may lie anywhere inside a Gaussian-distributed "cloud" centered on the message point. This is illustrated in Figure 5.7*a* for the case of a three-dimensional signal space. For a particular realization of the noise vector **w** (i.e., a particular point inside the random cloud of Figure 5.7*a*), the relationship between the observation vector **x** and the signal vector $\mathbf{s}_i$ is as illustrated in Figure 5.7*b*.

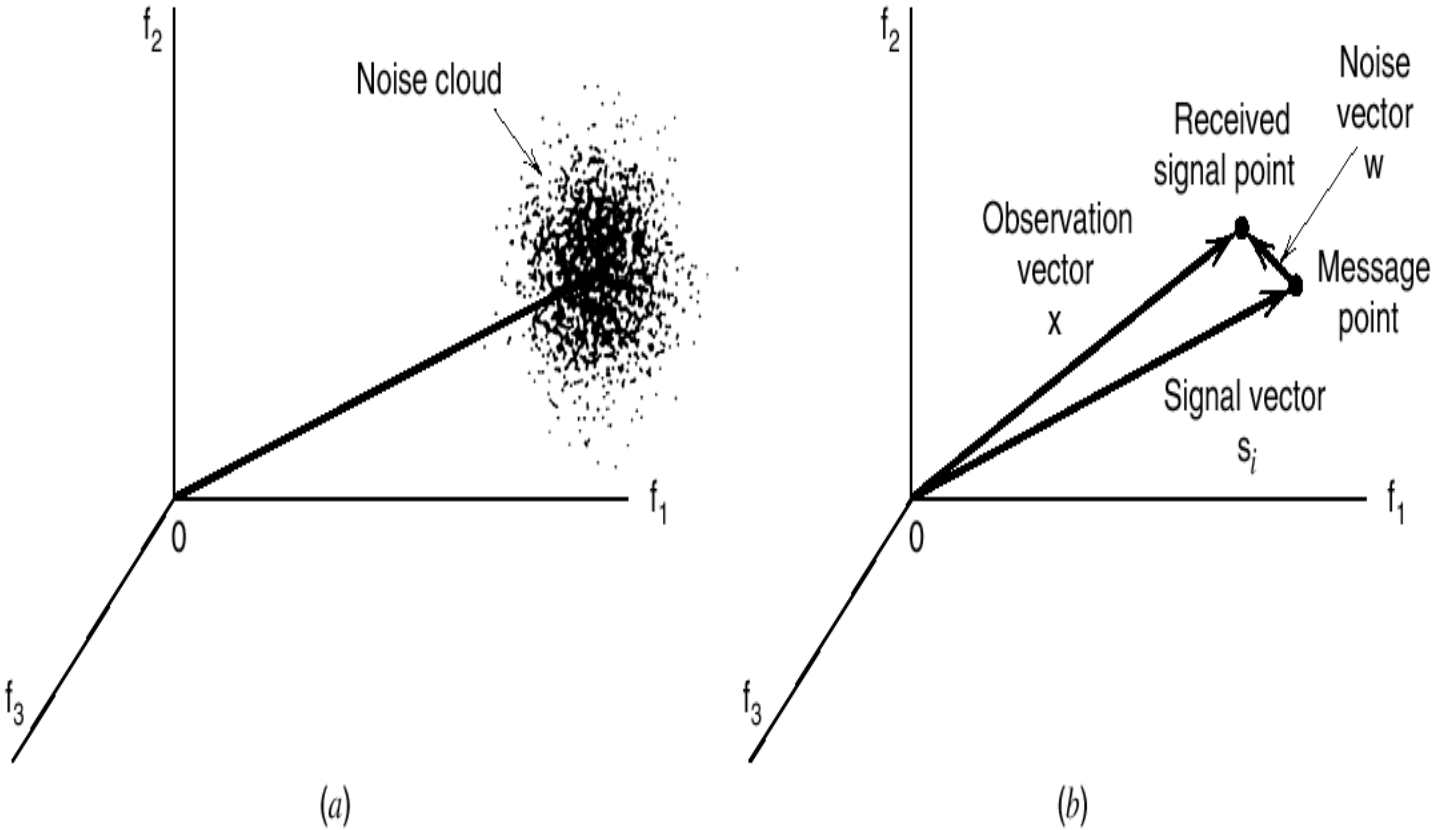


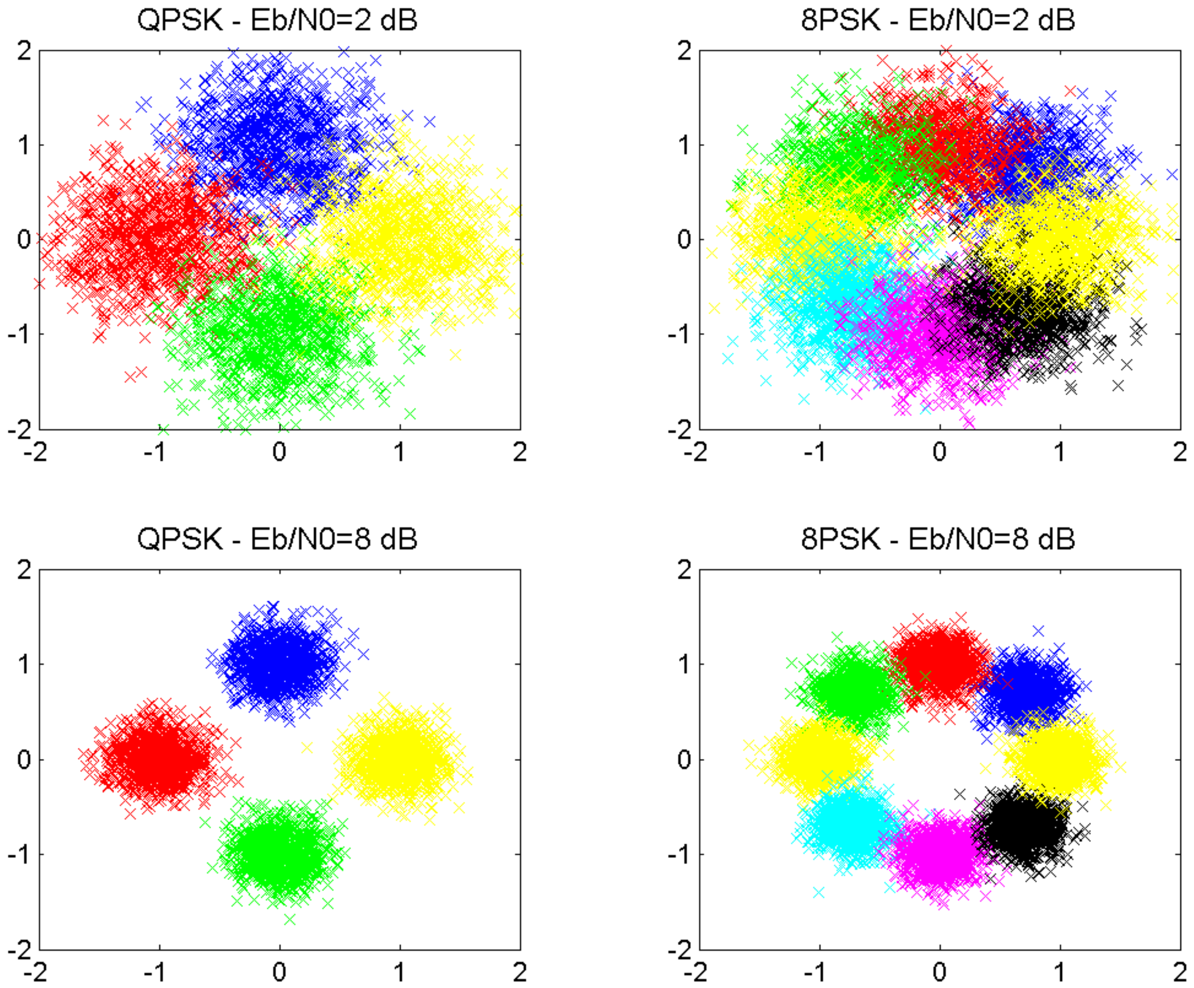
Figure 5.7 ***Illustrating the effect of noise perturbation, depicted in (a), on the location of the received signal point, depicted in (b).***

AWGN is

equivalent to an N-dimensional *vector channel* described by the observation vector

$$\mathbf{x} = \mathbf{s}_i + \mathbf{w}, \qquad i = 1, 2, \ldots, M \tag{5.48}$$

Example of samples of matched filter output for some bandpass modulation schemes



Suppose that, given the observation vector $\mathbf{x}$, we make the decision $\hat{m} = m_i$. The probability of error in this decision, which we denote by $P_e(m_i|\mathbf{x})$, is simply

$$
\begin{aligned}
P_e(m_i|\mathbf{x}) &= P(m_i \text{ not sent}|\mathbf{x}) \\
&= 1 - P(m_i \text{ sent}|\mathbf{x})
\end{aligned}
\tag{5.52}
$$

The decision-making criterion is to minimize the probability of error in mapping each given observation vector $\mathbf{x}$ into a decision. On the basis of Equation (5.52), we may therefore state the *optimum decision rule*:

$$
\begin{gathered}
\text{Set } \hat{m} = m_i \text{ if} \\
P(m_i \text{ sent}|\mathbf{x}) \geq P(m_k \text{ sent}|\mathbf{x}) \qquad \text{for all } k \neq i
\end{gathered}
\tag{5.53}
$$

graphical interpretation of the maximum likelihood decision

rule. Let Z denote the N-dimensional space of all possible observation vectors $\mathbf{x}$. We refer to this space as the *observation space*. Because we have assumed that the decision rule must say $\hat{m} = m_i$, where $i = 1, 2, \ldots, M$, the total observation space Z is correspondingly partitioned into *M-decision regions*, denoted by $Z_1, Z_2, \ldots, Z_M$. Accordingly, we may restate the decision rule of Equation (5.55) as follows:

Observation vector $\mathbf{x}$ lies in region Z_i if
the Euclidean distance $\| \mathbf{x} - \mathbf{s}_k \|$ is minimum for $k = i$ (5.59)

Equation (5.59) states that *the maximum likelihood decision rule is simply to choose the message point closest to the received signal point*, which is intuitively satisfying.

$$\sum_{j=1}^{N} (x_j - s_{kj})^2 = \| \mathbf{x} - \mathbf{s}_k \|^2$$

$\| \mathbf{x} - \mathbf{s}_k \|$ is the Euclidean distance

$$\sum_{j=1}^{N} (x_j - s_{kj})^2 = \| \mathbf{x} - \mathbf{s}_k \|^2$$

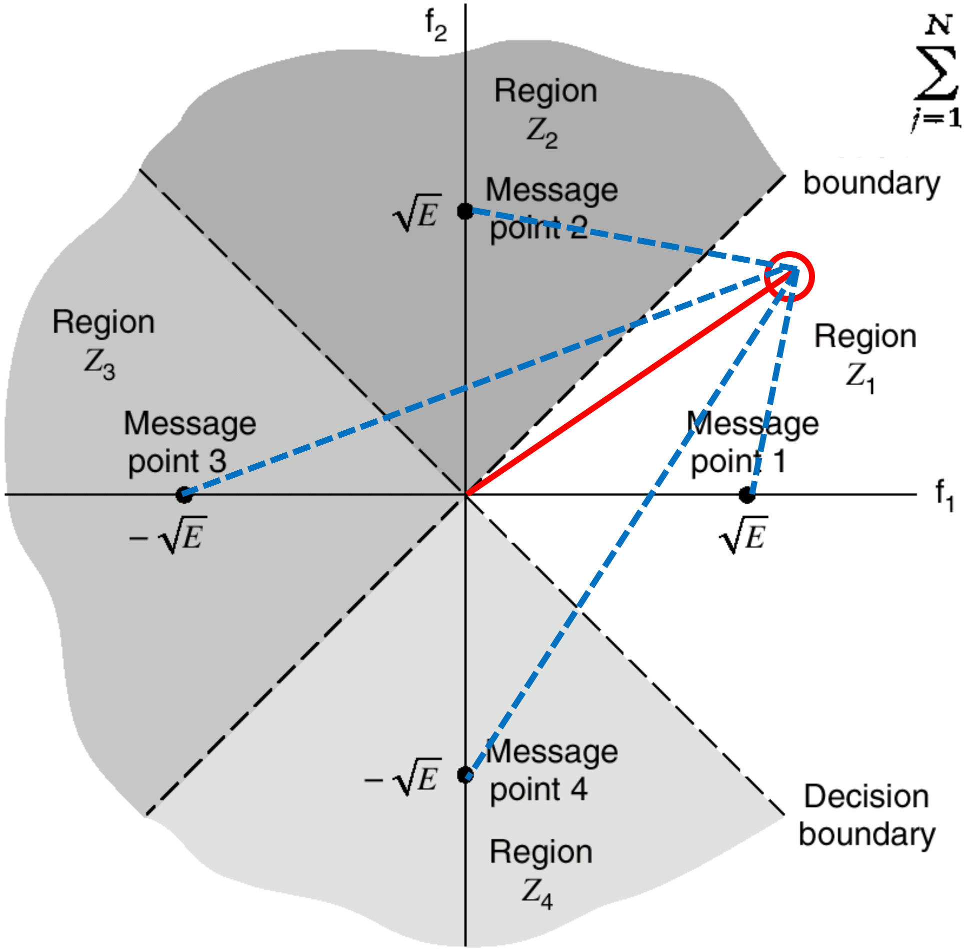


FIGURE 5.8 Illustrating the partitioning of the observation space into decision regions for the case when $N = 2$ and $M = 4$; it is assumed that the M transmitted symbols are equally likely.

$M = 4$ signals and $N = 2$ dimensions, assuming that the signals are transmitted with equal energy, E, and equal probability.

Week (6)- Lecture (2)
Signal-Space Analysis

5.6 *Correlation Receiver*

5.7 *Probability of Error*

5.6 *Correlation Receiver*

$\{s_i(t)\}$ are equally likely.

The correlation receiver consists of two parts :

* detector (correlator)
* decoder

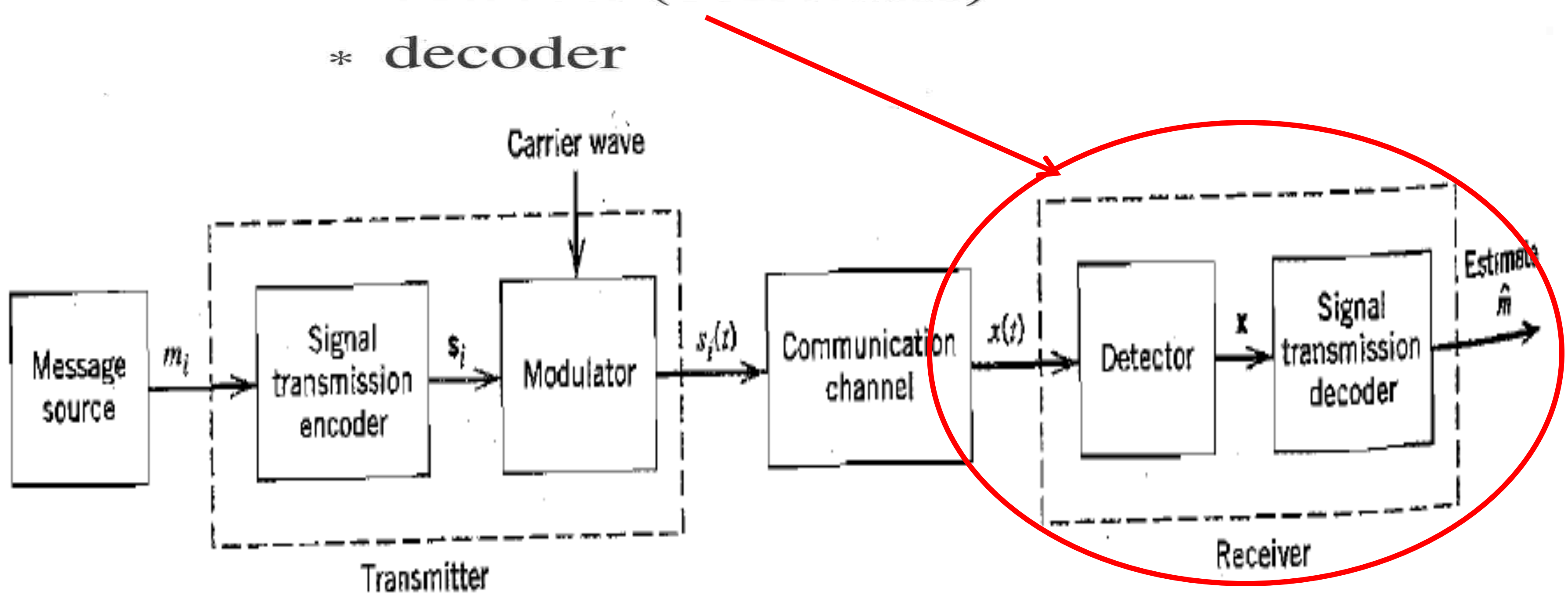


FIGURE 6.2 Functional model of passband data transmission system.

The optimum receiver of Figure 5.9 is commonly referred to as a *correlation receiver*.

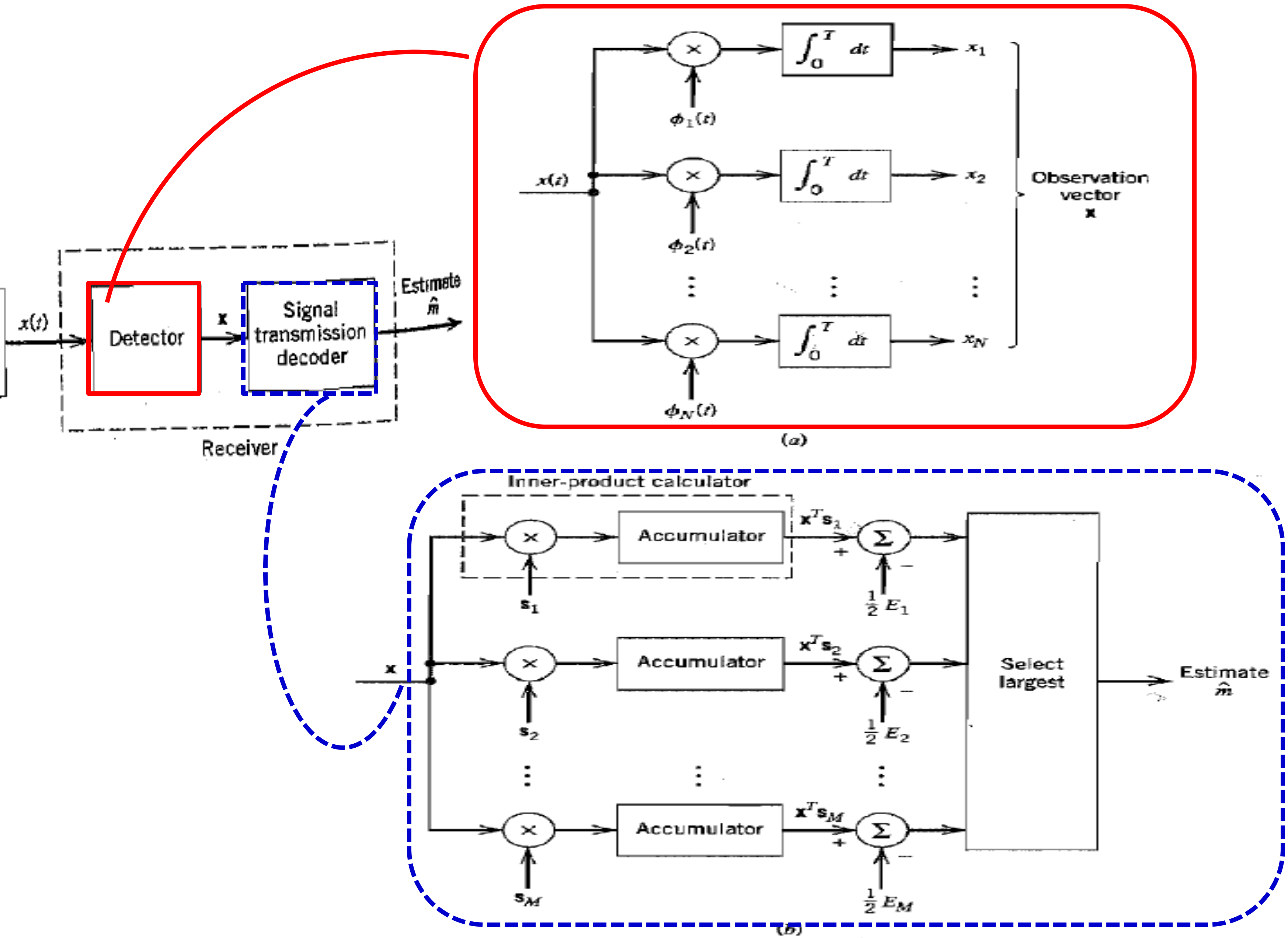
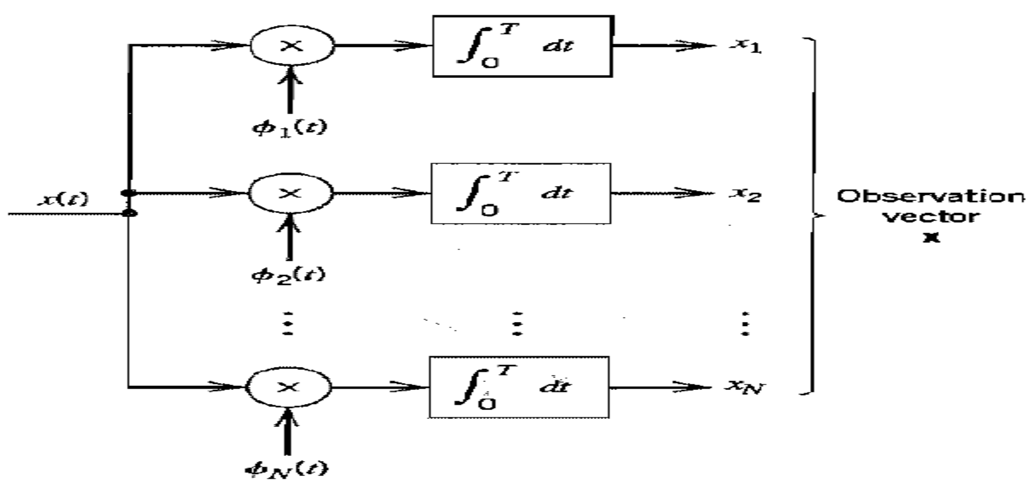


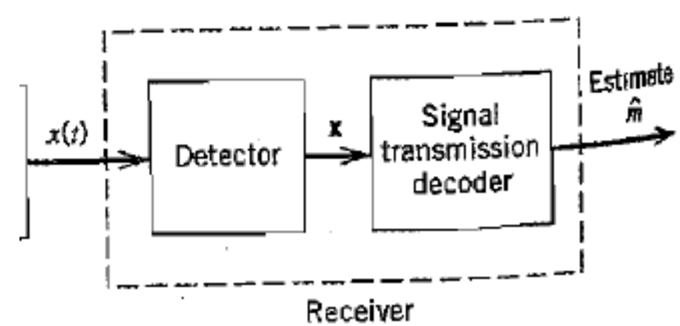
FIGURE 5.9 (*a*) Detector or demodulator. (*b*) Signal transmission decoder.

5.6 Correlation Receiver

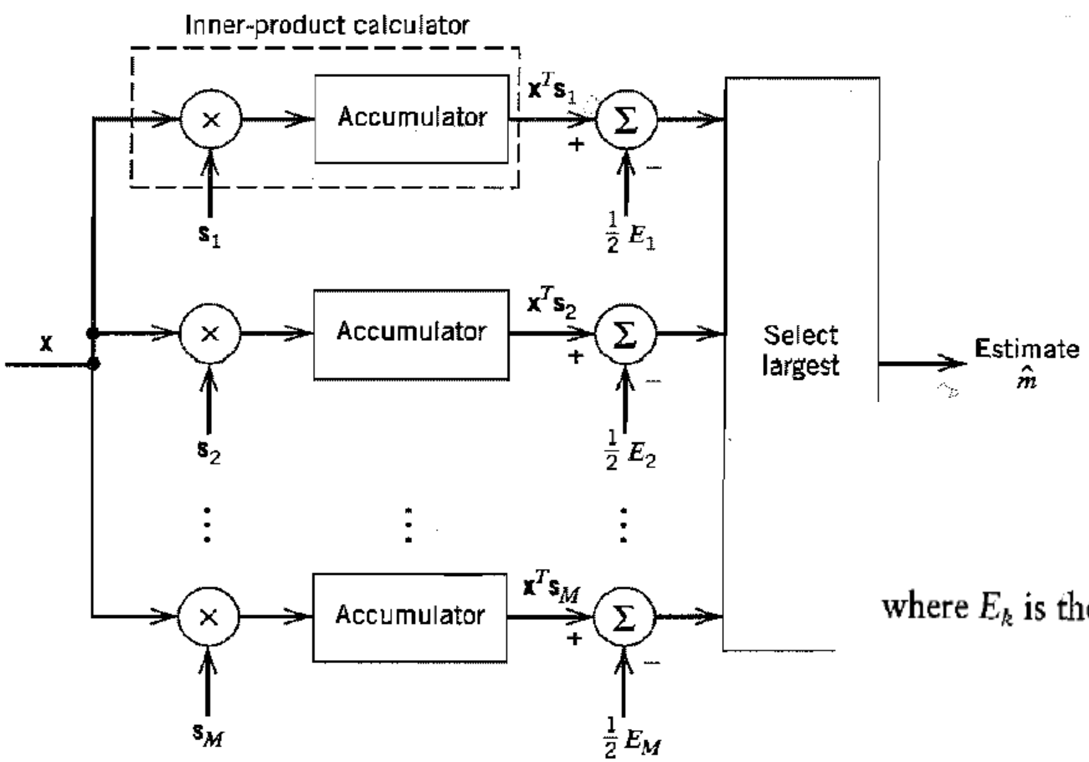
From the material presented in the previous sections, we find that for an AWGN channel and for the case when the transmitted signals $s_1(t), s_2, \ldots, s_M(t)$ are equally likely, the optimum receiver consists of two subsystems, which are detailed in Figure 5.9 and described here:

1. The *detector* part of the receiver is shown in Figure 5.9*a*. It consists of a bank of M *product-integrators* or *correlators*, supplied with a corresponding set of coherent reference signals or orthonormal basis functions $\phi_1(t), \phi_2(t), \ldots, \phi_N(t)$ that are generated locally. This bank of correlators operates on the received signal $x(t)$, $0 \le t \le T$, to produce the observation vector **x**.





2. The second part of the receiver, namely, the *signal transmission decoder* is shown in Figure 5.9*b*. It is implemented in the form of a maximum-likelihood decoder that operates on the observation vector **x** to produce an estimate, $\hat{m}$, of the transmitted symbol m_i, $i = 1, 2, \ldots, M$, in a way that would minimize the average probability of symbol error. In accordance with Equation (5.61), the N elements of the observation vector **x** are first multiplied by the corresponding N elements of each of the M signal vectors $\mathbf{s}_1, \mathbf{s}_2, \ldots, \mathbf{s}_M$, and the resulting products are successively summed in accumulators to form the corresponding set of inner products $\{\mathbf{x}^T\mathbf{s}_k \mid k = 1, 2, \ldots, M\}$. Next, the inner products are corrected for the fact that the transmitted signal energies may be unequal. Finally, the largest in the resulting set of numbers is selected and an appropriate decision on the transmitted message is made.



Observation vector **x** lies in region Z_i if the Euclidean distance $\|\mathbf{x} - \mathbf{s}_k\|$ is minimum for $k = i$

Observation vector **x** lies in region Z_i if

$$\sum_{j=1}^{N} x_j s_{kj} - \frac{1}{2} E_k \text{ is maximum for } k = i$$

where E_k is the energy of the transmitted signal $s_k(t)$:

$$E_k = \sum_{j=1}^{N} s_{kj}^2$$

▶ EXAMPLE 4.1 Matched Filter for Rectangular Pulse

Consider a signal $g(t)$ in the form of a rectangular pulse of amplitude A and duration T, as shown in Figure 4.2*a*. In this example, the impulse response $h(t)$ of the matched filter has exactly the same waveform as the signal itself. The output signal $g_o(t)$ of the matched filter produced in response to the input signal $g(t)$ has a triangular waveform, as shown in Figure 4.2*b*.

The maximum value of the output signal $g_o(t)$ is equal to kA^2T, which is the energy of the input signal $g(t)$ scaled by the factor k; this maximum value occurs at $t = T$, as indicated in Figure 4.2*b*.

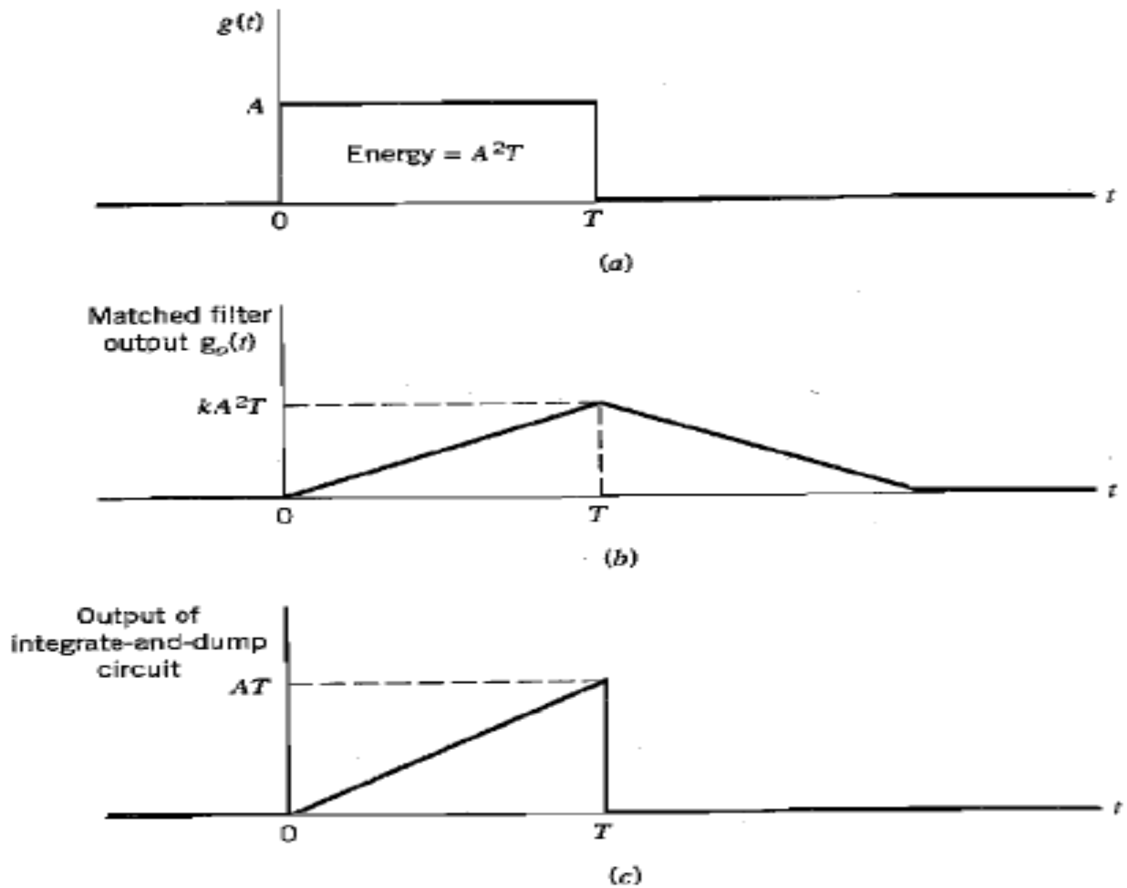
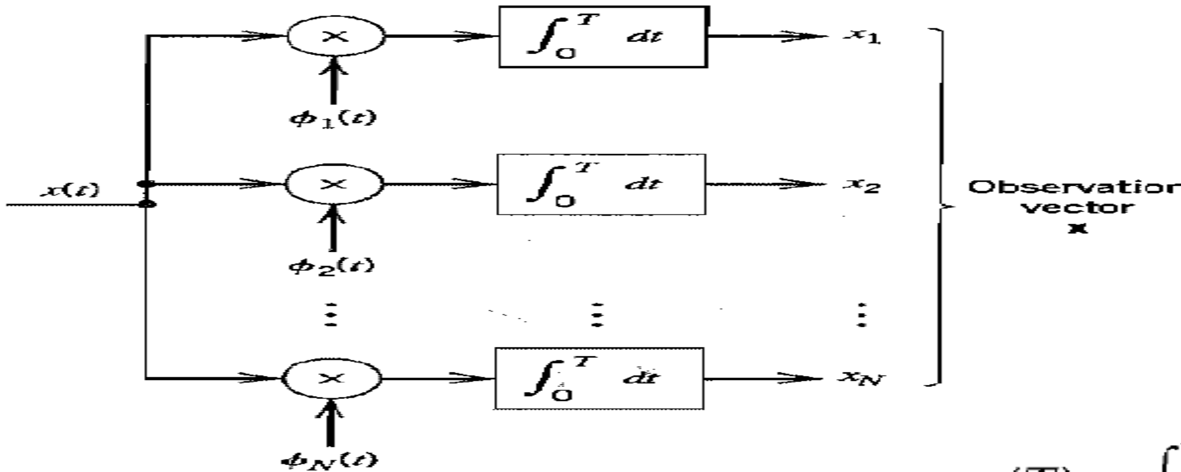


FIGURE 4.2 (*a*) Rectangular pulse. (*b*) Matched filter output. (*c*) Integrator output.



$$y_j(T) = \int_0^T x(\tau)\phi_j(\tau)d\tau$$

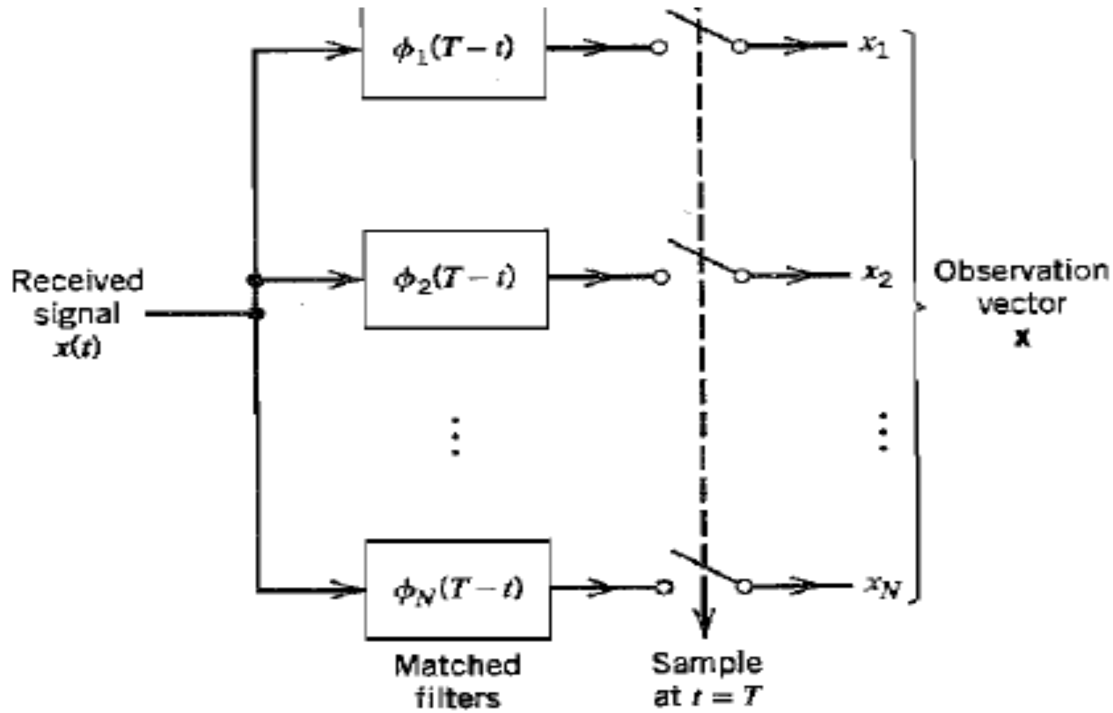


FIGURE 5.10 Detector part of matched filter receiver; the signal transmission decoder is as shown in Fig. 5.9*b*.

5.7 Probability of Error

readily see that the *average probability of symbol error*, P_e is

$$P_e = \sum_{i=1}^{M} p_i \, P(\mathbf{x} \text{ does not lie in } Z_i | m_i \text{ sent})$$

$$= \frac{1}{M} \sum_{i=1}^{M} P(\mathbf{x} \text{ does not lie in } Z_i | m_i \text{ sent}) \quad (5.67)$$

$$= 1 - \frac{1}{M} \sum_{i=1}^{M} P(\mathbf{x} \text{ lies in } Z_i | m_i \text{ sent})$$

Pc

where we have used standard notation to denote the probability of an event and the conditional probability of an event. Since $\mathbf{x}$ is the sample value of random vector $\mathbf{X}$, we may rewrite Equation (5.67) in terms of the likelihood function (when m_i is sent) as follows:

$$P_e = 1 - \frac{1}{M} \sum_{i=1}^{M} \int_{Z_i} f_{\mathbf{X}}(\mathbf{x}|m_i) \, d\mathbf{x} \quad (5.68)$$

summary

5.7 Probability of Error

The average prob. of symbol error

$$P_e = \sum_{i=1}^{M} p_i P(\text{x does not lie in } Z_i \mid m_i \text{ sent})$$

$$= \frac{1}{M}\sum_{i=1}^{M} P(\text{x does not lie in } Z_i \mid m_i \text{ sent}) \quad (5.67)$$

$$= 1 - \frac{1}{M}\sum_{i=1}^{M} P(\text{x lies in } Z_i \mid m_i \text{ sent}) \quad (5.68)$$