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$$N = 2^n$$

$$\delta_i = \frac{1}{2^{n-i-1}}$$

$$x(k) = \sum_{m=0}^{N-1} x(m) e^{-j \frac{2\pi km}{N}}$$

$$|X_{n-i}(k)| = \frac{2\delta_{n-i}}{N} \cdot \frac{\left| \sin\left(\frac{\pi k}{2}\right) \right|}{\sin\left(\frac{m\pi k}{N}\right)}, \quad (1)$$

$$i = 1, 2, \dots, n; \quad m = 2^{n-i-1}.$$

$$K_{HD1} = 10 \lg \frac{U_{20}^2 + U_{30}^2 + \dots + U_{N0}^2}{U_1^2}, \quad (2)$$

$$D_r = -K_{HD},$$

(1) (2),

$\pm U_{f_s}$

$j-$

$n-$

$$p(j) = \frac{1}{\pi} \left[\arcsin \frac{U_{f_s}(j - 2^{n-1})}{U_m \cdot 2^n} - \arcsin \frac{U_{f_s}(j - 1 - 2^{n-1})}{U_m \cdot 2^n} \right], \quad (3)$$

U_m -

j -

$$M_t(j) = p(j) \cdot M_\Sigma. \quad (4)$$

$$\delta_d(j) = \frac{M_r(j)}{p(j) \cdot M_\Sigma} - 1. \quad (5)$$

$$p_{\min} = \frac{2}{\pi \cdot 2^{n-1}}. \quad (6)$$

$$\sigma = \sqrt{p_{\min} \cdot M_\Sigma} \cdot M, \quad 0,1$$

(),

$$M_\Sigma \geq 50 \cdot \pi \cdot 2^{n-1}. \quad (7)$$

$$X_w(k) = \sum_{m=0}^{N-1} x(m) \cdot \text{Wal}(k, m), \quad \text{Wal}(k, m) -$$

$$C(\mu, m) = \text{sign}[\cos(2^\mu \cdot \pi \cdot m)]:$$

$$\text{Wal}_w(k, m) = \prod_{\mu=0}^{N-1} [C(\mu, m)]^{g_\mu}, \quad (8)$$

g_μ -

$$N = 2^n - 1$$

$$X_w(0) \quad m+1 \quad X_w(k) -$$

Wal(1,0); Wal(3,0), . 1.
n = 4

$N = 16:$

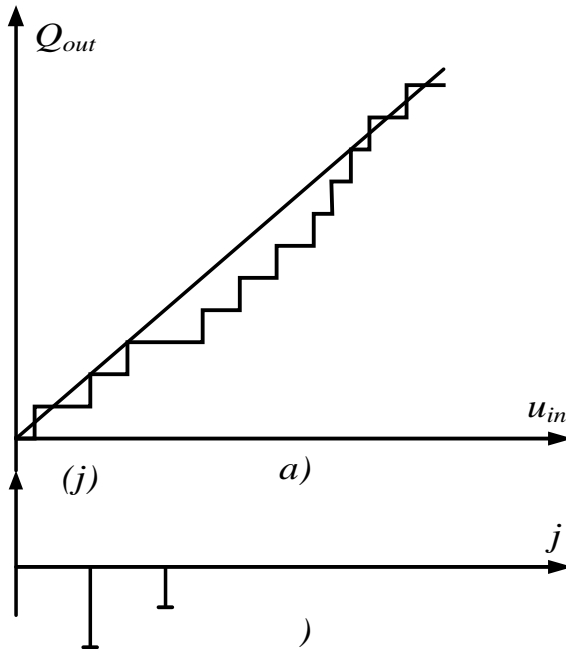
$$X_w(1) = -1 \cdot \frac{1}{N} \cdot \delta_{n-1} \cdot 0,5N = -0,5 \cdot \delta_3,$$

$$X_w(3) = -1 \cdot \frac{1}{N} \cdot (\delta_{n-2} \cdot 0,25N + \delta_{n-2} \cdot 0,25N) = -0,5 \cdot \delta_2.$$
(9)

, , i-

$$X_w(k) = X[2^{n-i} - 1] = -0,5 \cdot \delta_i,$$
(10)

$i = 0, 1, \dots, n-1.$



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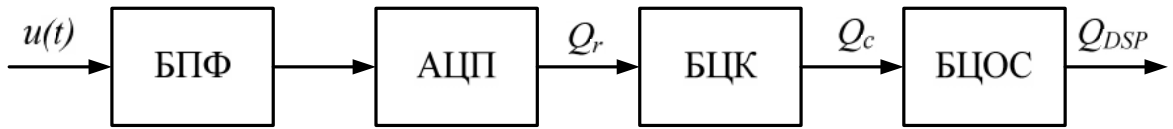
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δ_i

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$$Q_c = Q_r + \sum_{i=1}^n \delta_i \cdot \alpha_{ri}.$$
(11)



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$u(t)$,

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 Q_r

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Q_c (),

Q_{DSP} .

u_{in}

u_{fs} :

$$D = 20 \lg \left(\frac{u_{in}}{u_{fs}} \right) + 6n - 20 \lg k + 4,8 - 20 \lg \left(1 + \frac{2\delta - \Delta u}{q} \right), \quad (12)$$

k - -

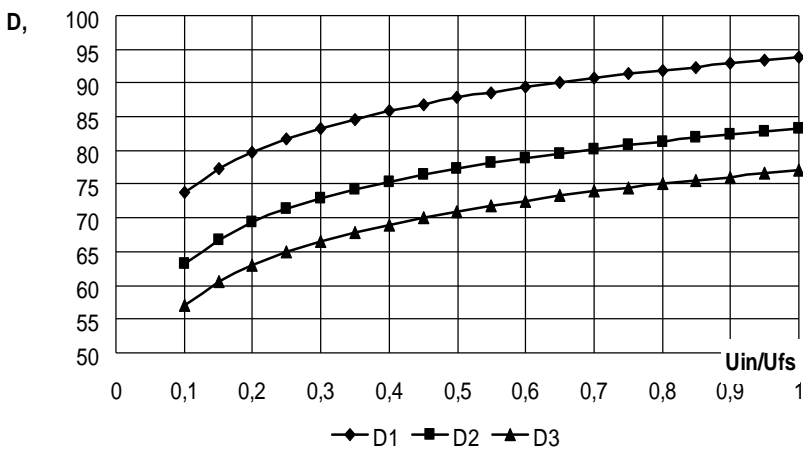
Δu

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$$\sigma_L = \frac{u_m \cdot \pi}{2q} \cdot \frac{1}{\sqrt{M}} \cdot 10^{\frac{L}{10}}. \quad (13)$$

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$$\frac{u_{in}}{u_{fs}} = 1 \quad 94 \quad ,$$

D_{max}

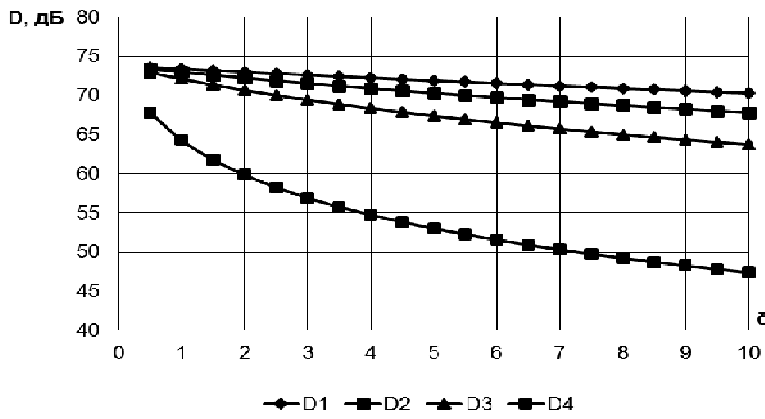
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$$D = f(\delta) \quad 12-$$

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D1
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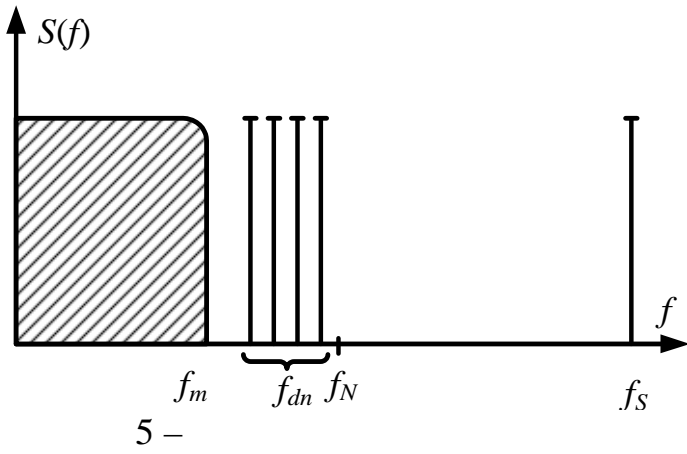
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$$\Delta f_{d_n} = 0,9(0,5 f_s - f_m), \quad (14)$$

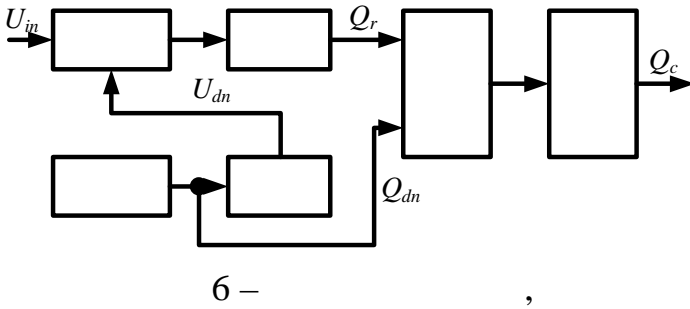
$f_m -$
. 5

U_{fs}



U_s ,
 U_m - ,

$$U_{dn} = 0,5U_{fs} \left(1 - \frac{U_s}{U_m} \right). \quad (15)$$



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U_{dn}

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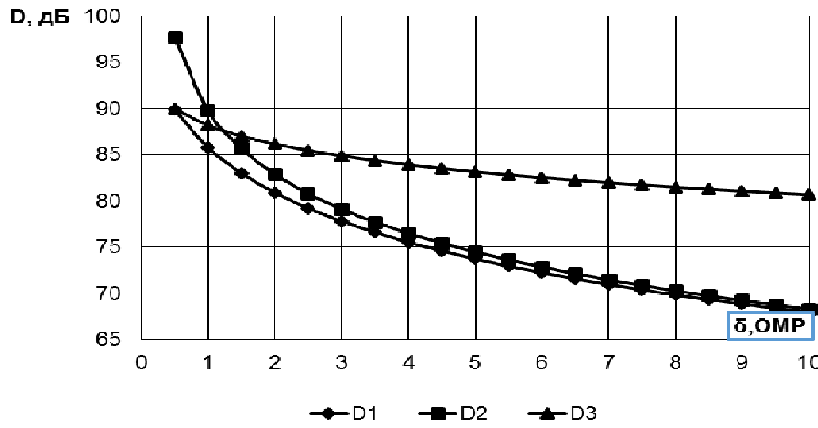
U_{in}

Q_r ()
 Q_{dn} () .

Δf_{dn} .

$$D = 20 \lg \frac{U_{in} - U_{dn}}{U_{fs}} + 6n - 20 \lg k + 4,8 - 20 \lg \left[1 + E \left(\frac{3\delta}{q} \right) \right] + 10 \lg \frac{f_s}{2f_{in}}. \quad (16)$$

. 7



$U_{dn} = 0.$

$U_{dn} = 1 \text{ OMP}.$

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16-

(17), $U_{dn} \gg 1 \text{ OMP}.$

$\delta = 10 \text{ OMP}$

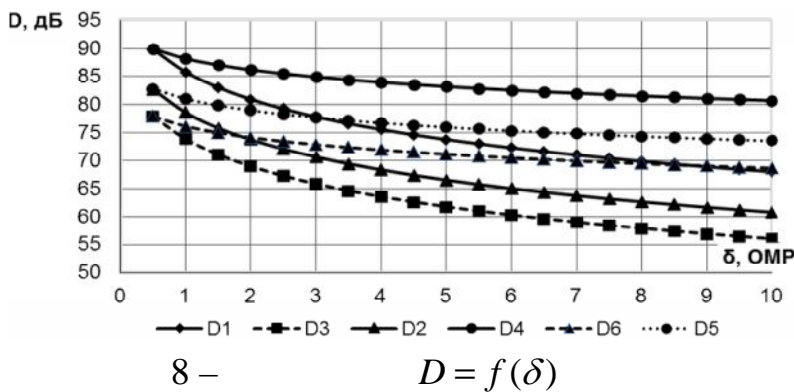
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(0,5 ÷ 1) .

98 90 ,
90 86 .
.8

6 ÷ 14



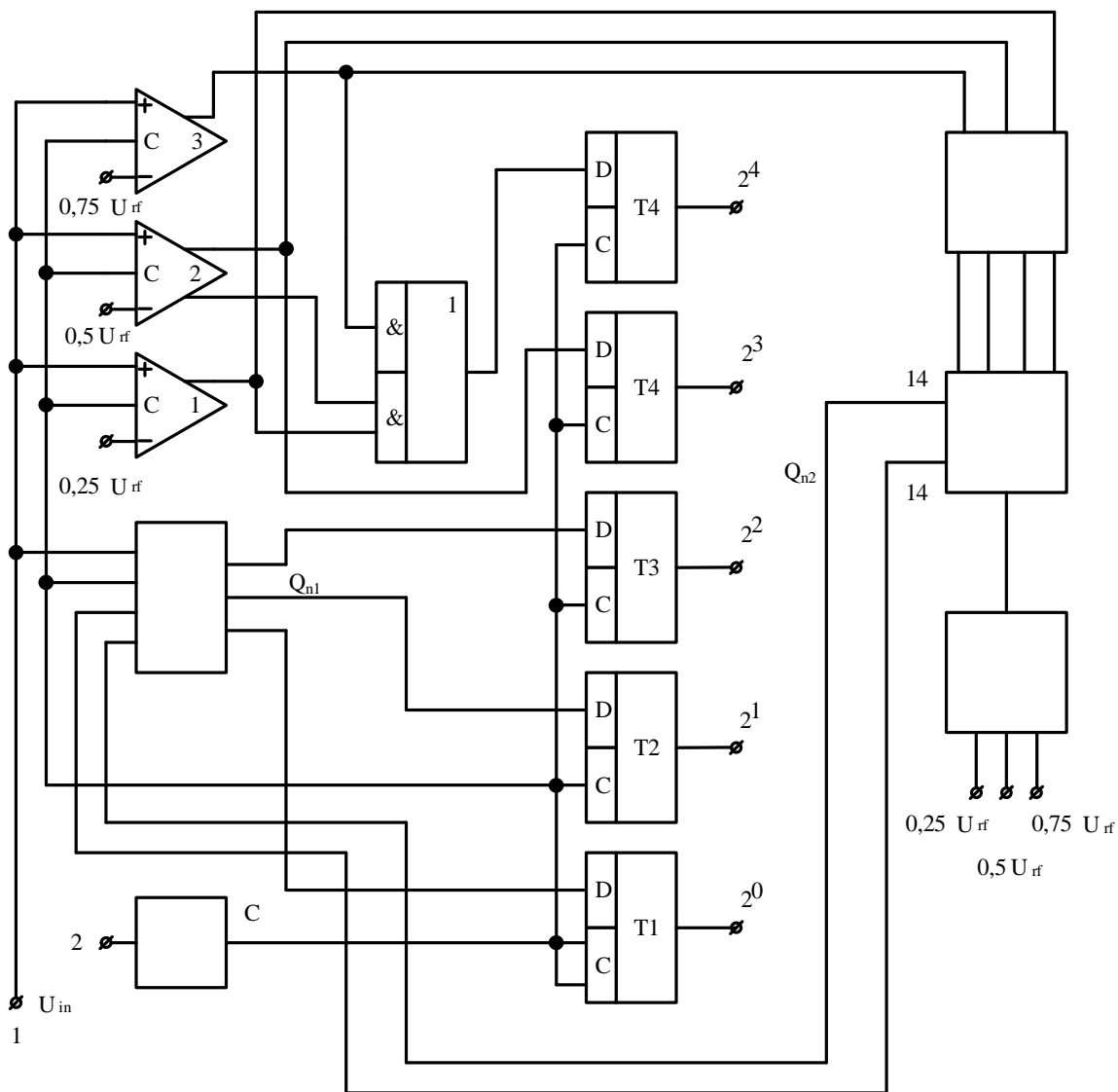
$U_{in} = 0,25U_{fs}$

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$D = f(\delta)$

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$2^{n-n_1} - 1.$

$$Q_{BADC} = \frac{10^{\frac{6n+1,8}{20}}}{(2^{n_1} + 2^{n_2} - 2) \cdot \frac{t_c}{T_s}} \quad (17)$$

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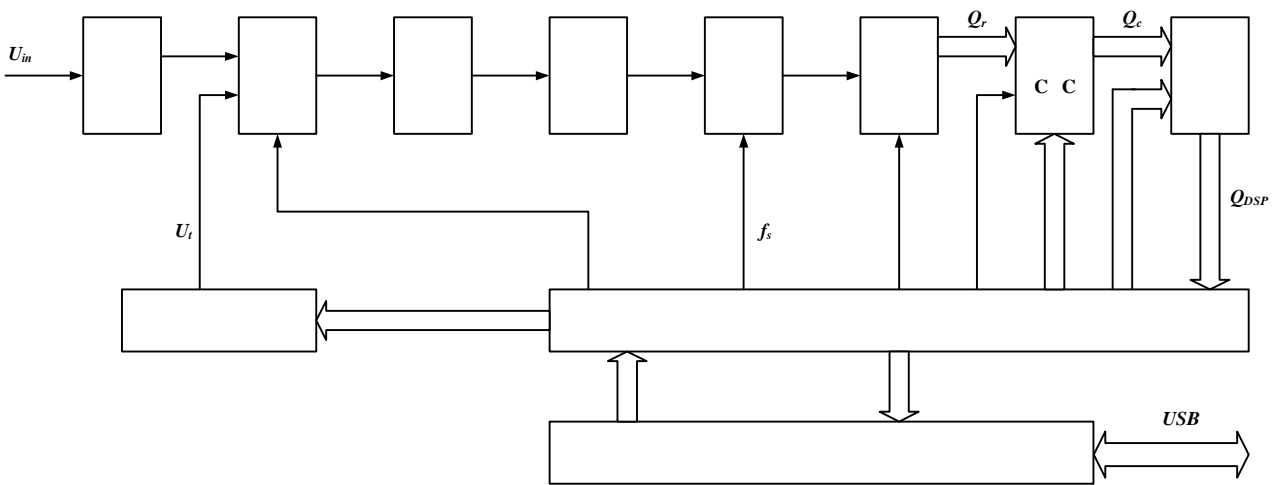
WF-
 $X_w(k)$

$X_F(k)$

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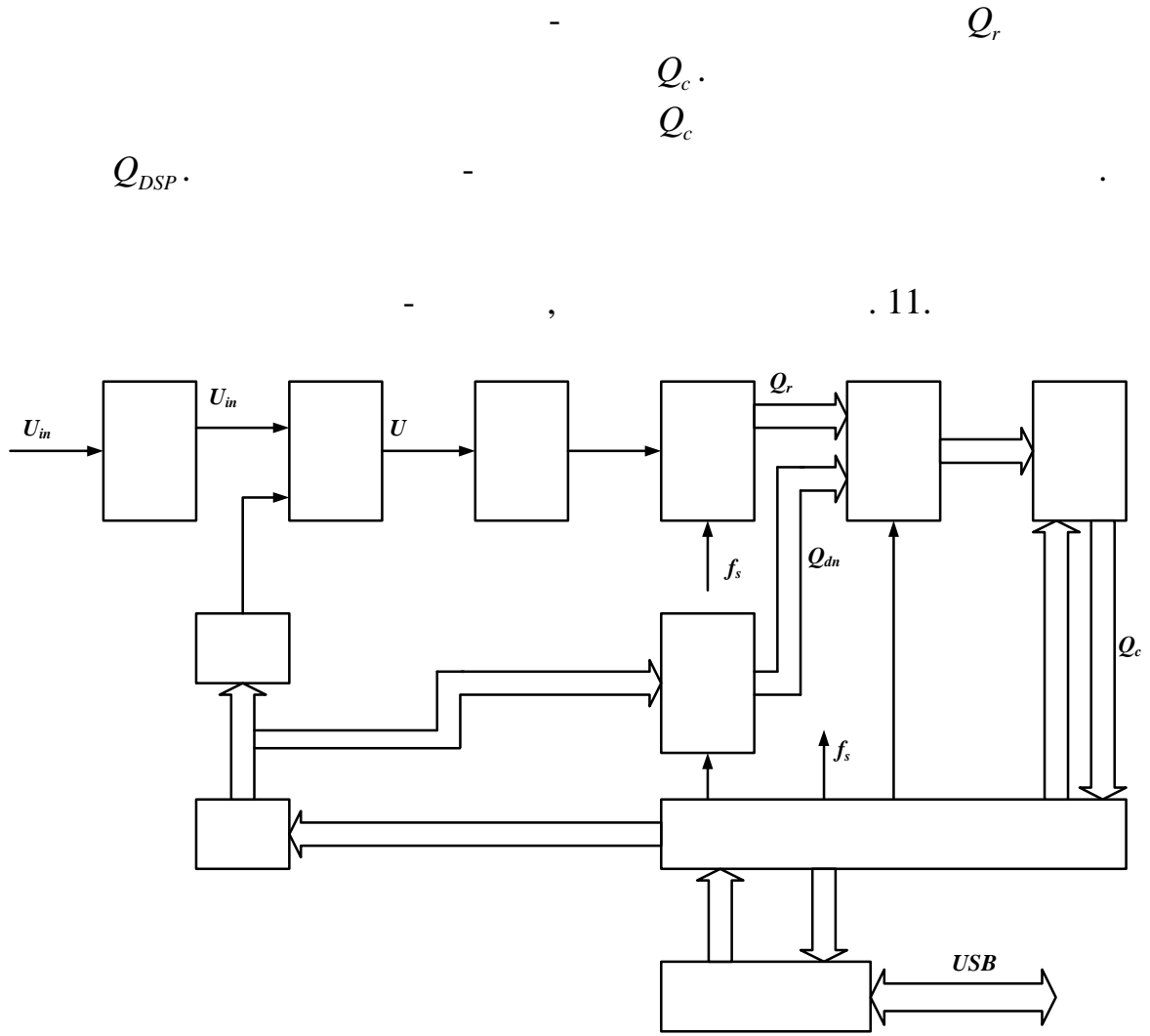
2,5 ÷ 2,88.

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Q_{DSP}

Q_c
 Q_c

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U_{dn}

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ABSTRACT

Stalchenko O.V Analog-digital high frequency signals conversion paths with non-linearity correction. – Manuscript.

The thesis submitted for the candidate of science degree by specialty 05.13.05 – computer systems and components. – Vinnytsia National Technical University, Vinnytsia. – 2015.

The thesis is devoted to developing dynamic range expansion methods for the analog-digital path (ADP) of computer system HF signals by correcting the path conversion characteristics () non-linearity.

The mathematical model for non-linearity of the analog-digital path used in computer systems processing HF signals is improved. The model takes into account every quantization level impact due, accordingly simplifies process of the ADP real dynamic range determination and increases obviousness of signal harmonic distortion estimation.

The new method of digital correction for the HF signals analog-digital path non-linearity is proposed, it uses processing test signal samples at time and frequency representations to form correcting components and its dynamic range expansion.

Analytical expressions for the ADP dynamic range estimation with correction are obtained, which consider noise power, input signals parameters and adjustment formation accuracy.

The method of HF signals analog-digital conversion with adding an auxiliary noise-type signal is improved, it uses narrow-band noise as auxiliary one, whose spectrum is out of the desired signal frequency range and its amplitude exceeds the ADC quantization step.

The ADP structure using the non-linearity digital correction method and the HF signals ADP structure based on the modified method of the analog-digital conversion with adding a noise-type signal are developed on a base of the offered technical strategy.

Keywords: analog-digital path, conversion characteristics non-linearity, high-frequency signals, non-linearity correction, HF signals digital processing.

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