

CORDIC Background (2A)

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CORDIC Background

1.A survey of CORDIC algorithms for FPGAs, Ray Andraka,
www.andraka.com/cordic.htm

Vector Rotation (1)

$$x' = x \cos \phi - y \sin \phi$$

$$y' = y \cos \phi + x \sin \phi$$

$$x' = \cos \phi \cdot [x - y \tan \phi]$$

$$y' = \cos \phi \cdot [y + x \tan \phi]$$

$$x_{i+1} = K_i \cdot [x_i - y_i \cdot d_i \cdot 2^{-i}]$$

$$y_{i+1} = K_i \cdot [y_i + x_i \cdot d_i \cdot 2^{-i}]$$

$$K_i = \cos \phi_i = \cos(\tan^{-1}(2^{-i}))$$

$$= \frac{1}{\sqrt{1 + 2^{-2i}}}$$

$$d_i = \pm 1$$

Restrict rotation angle $\Rightarrow \tan \phi = \pm 2^{-i}$

Multiplication \Rightarrow simple shift

$$y \cdot \tan \phi$$

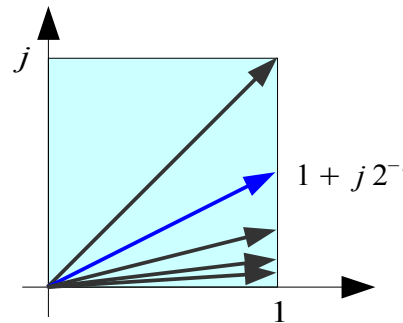
$$y \cdot 2^{-i}$$

$$x \cdot \tan \phi$$

$$x \cdot 2^{-i}$$

regardless of direction $\Rightarrow \cos(\phi) = \cos(-\phi)$

Allowed Rotation Angles



$$\tan \phi \Rightarrow 2^{-i}$$

$$\cos \phi \Rightarrow \frac{1}{\sqrt{1 + 2^{-2i}}}$$

$$K_i \leq 1$$

$$(K_i \leftarrow \cos \phi)$$

Vector Rotation (2)

$$x_{i+1} = K_i \cdot [x_i - y_i \cdot d_i \cdot 2^{-i}]$$

$$y_{i+1} = K_i \cdot [y_i + x_i \cdot d_i \cdot 2^{-i}]$$

$$K_i = \cos \phi_i = \cos(\tan^{-1}(2^{-i}))$$

$$= \frac{1}{\sqrt{1 + 2^{-2i}}} \quad K_i \leq 1$$

$$d_i = \pm 1$$

$$x_{i+1}^2 = K_i^2 \cdot [x_i^2 + y_i^2 \cdot 2^{-2i} - 2x_i y_i d_i \cdot 2^{-i}]$$

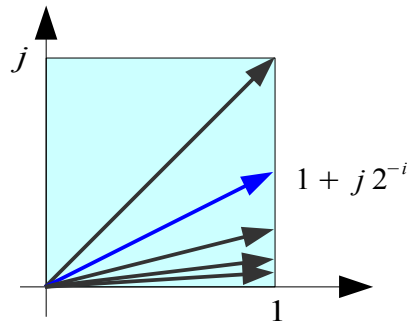
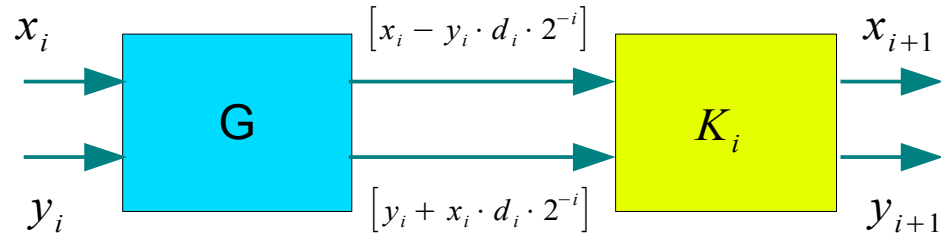
$$y_{i+1}^2 = K_i^2 \cdot [y_i^2 + x_i^2 \cdot 2^{-2i} + 2x_i y_i d_i \cdot 2^{-i}]$$

$$x_{i+1}^2 + y_{i+1}^2 = K_i^2 \cdot (1 + 2^{-2i}) \cdot (x_i^2 + y_i^2)$$

$$G \cdot K_i = 1$$

$$K_i \leq 1$$

$$G > 1$$



$$\tan \phi \rightarrow 2^{-i}$$

$$\cos \phi \rightarrow \frac{1}{\sqrt{1 + 2^{-2i}}}$$

CORDIC Gain : *growing in magnitude*

$$A_n = \prod_{i=1}^n \frac{1}{K_i} = \prod_{i=1}^n \sqrt{1 + 2^{-2i}} \rightarrow 1.647$$

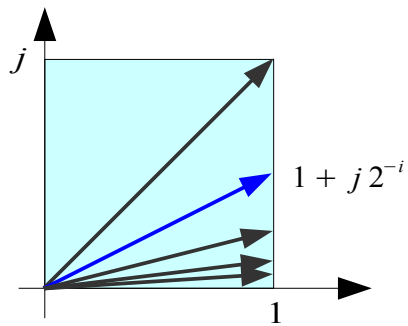
Vector Rotation (3)

$$x_{i+1} = K_i \cdot [x_i - y_i \cdot d_i \cdot 2^{-i}]$$

$$y_{i+1} = K_i \cdot [y_i + x_i \cdot d_i \cdot 2^{-i}]$$

$$K_i = 1 / \sqrt{1 + 2^{-2i}} \quad \leftarrow \cos(\phi_i)$$

$$d_i = \pm 1$$



$$\tan \phi \rightarrow 2^{-i}$$

$$\cos \phi \rightarrow \frac{1}{\sqrt{1 + 2^{-2i}}}$$

Without Scale Constants K_i

$$x_{i+1} = [x_i - y_i \cdot d_i \cdot 2^{-i}]$$

$$y_{i+1} = [y_i + x_i \cdot d_i \cdot 2^{-i}]$$

$$d_i = \pm 1$$

CORDIC Gain : *growing in magnitude*

$$A_n = \prod_{i=1}^n \frac{1}{K_i} = \prod_{i=1}^n \sqrt{1 + 2^{-2i}} \rightarrow 1.647$$

$$1 / K_i = \sqrt{1 + 2^{-2i}}$$

For correction

Multiplying K_i 's as a processing gain

$$\prod_{i=1}^n K_i = \prod_{i=1}^n \frac{1}{\sqrt{1 + 2^{-2i}}} \rightarrow 0.6073$$

Angle Accumulator

Rotation Mode

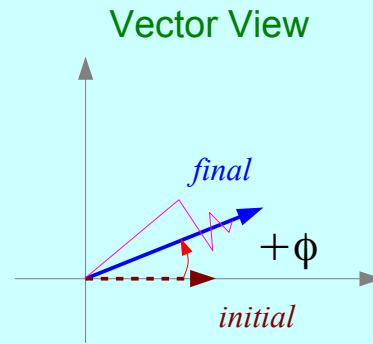
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

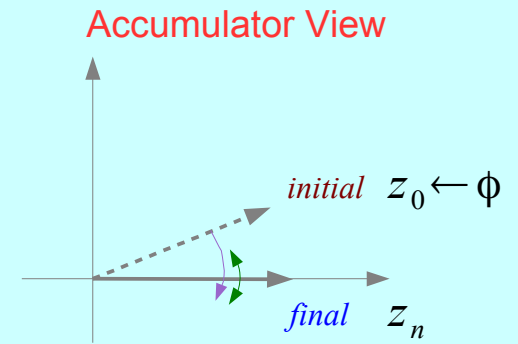
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle



Subtract angles at each step

Vectoring Mode

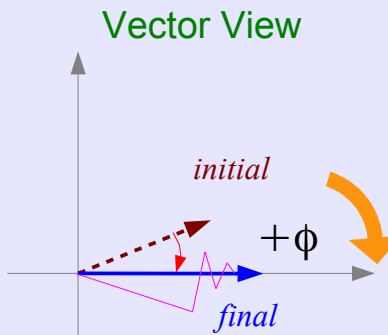
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

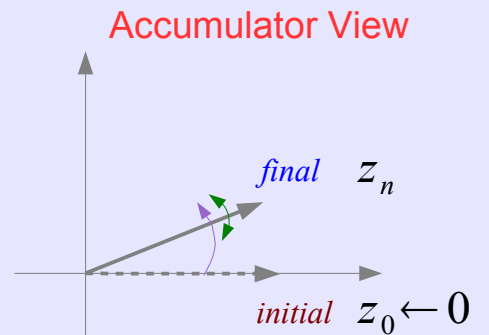
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

Rotation Mode

Rotation Mode

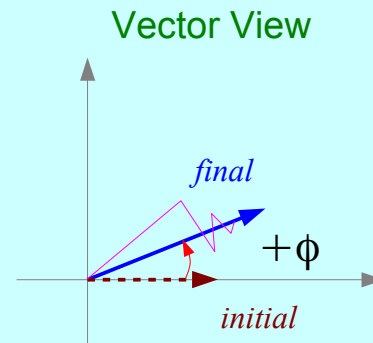
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

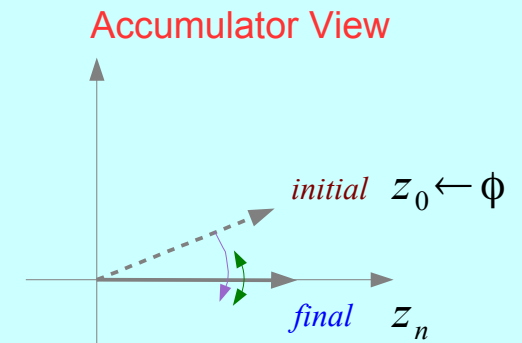
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle



Subtract angles at each step

$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$

$$x_n = A_n [x_0 \cos z_0 - y_0 \sin z_0]$$

$$y_n = A_n [y_0 \cos z_0 + x_0 \sin z_0]$$

$$z_n = 0$$

$$A_n = \prod_{i=1}^n \sqrt{1 + 2^{-2i}}$$

Vectoring Mode

Vectoring Mode

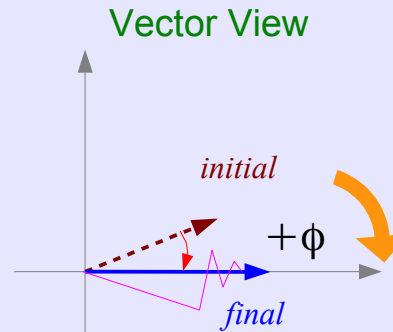
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

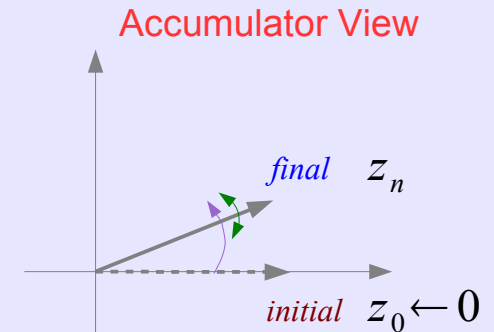
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$

$$x_n = A_n \sqrt{x_0^2 + y_0^2}$$

$$y_n = 0$$

$$z_n = z_0 + \tan^{-1}(y_0/x_0)$$

$$A_n = \prod_{i=1}^n \sqrt{1 + 2^{-2i}}$$

Angle Accumulator – Rotation Mode

Rotation Mode

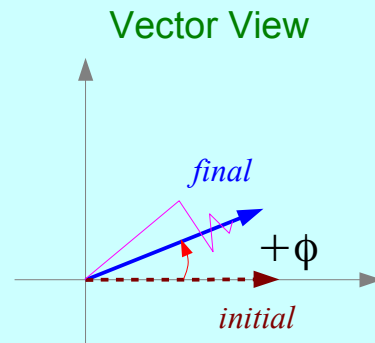
$$z_0 \leftarrow \phi \quad (\text{input})$$

$$z_n \rightarrow 0$$

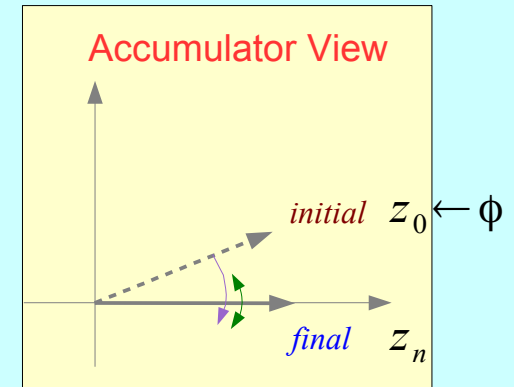
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle



Subtract angles at each step

$$z_i < 0$$

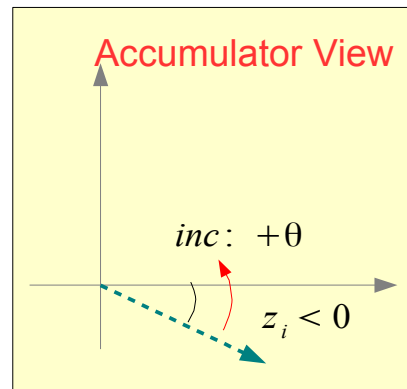
Increase Angle $d_i = -1$

$$z_{i+1} = z_i + \tan^{-1}(2^{-i})$$

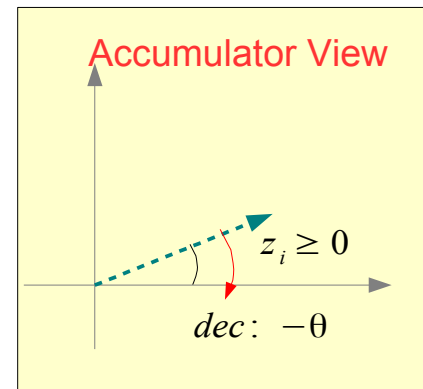
$$z_i \geq 0$$

Decrease Angle $d_i = +1$

$$z_{i+1} = z_i - \tan^{-1}(2^{-i})$$



$z_i < 0$
Increase Angle $+θ$



$z_i \geq 0$
Decreases Angle $-θ$

Angle Accumulator – Vectoring Mode

Vectoring Mode

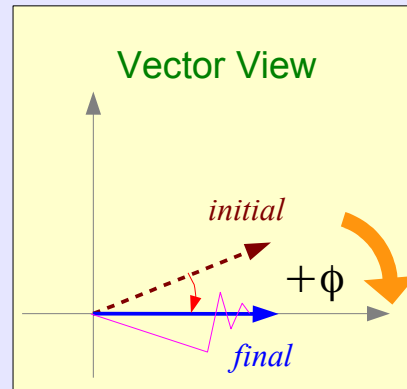
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

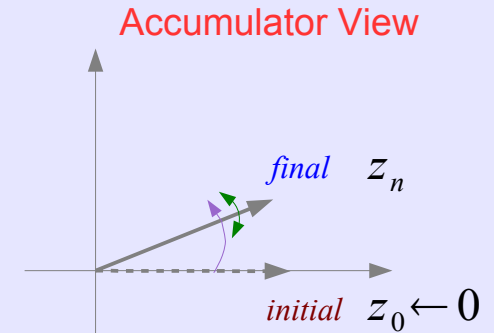
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

$$y_i < 0$$

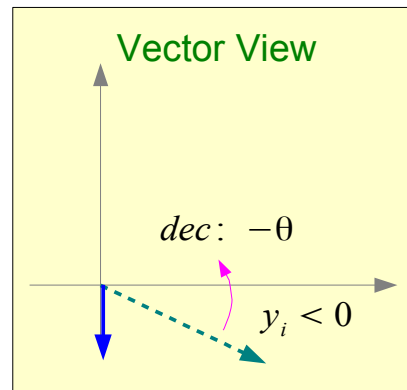
Decrease Angle $d_i = +1$

$$z_{i+1} = z_i - \tan^{-1}(2^{-i})$$

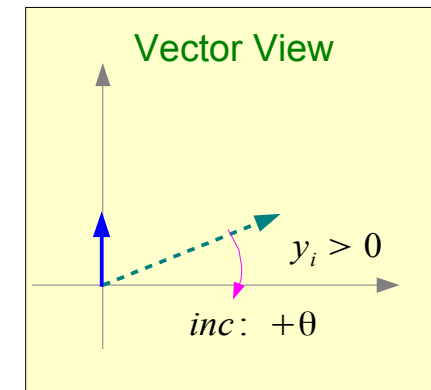
$$y_i > 0$$

Increase Angle $d_i = -1$

$$z_{i+1} = z_i + \tan^{-1}(2^{-i})$$



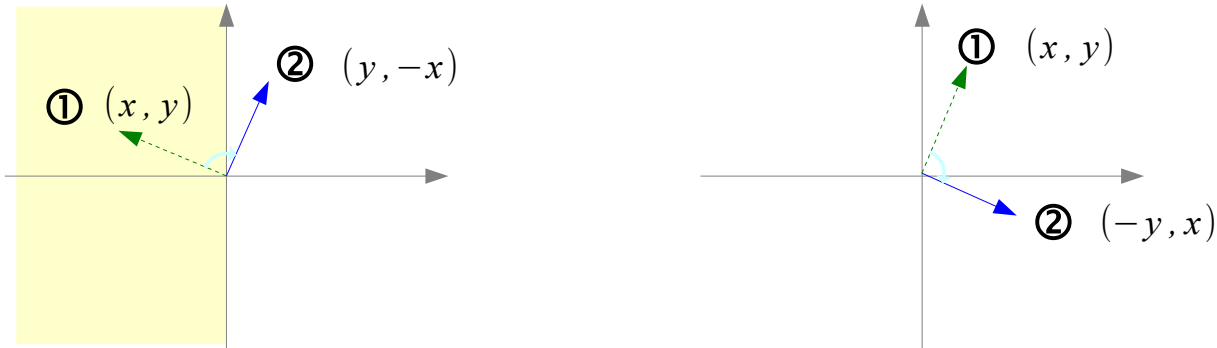
$y_i < 0$
Decrease Angle $-\theta$



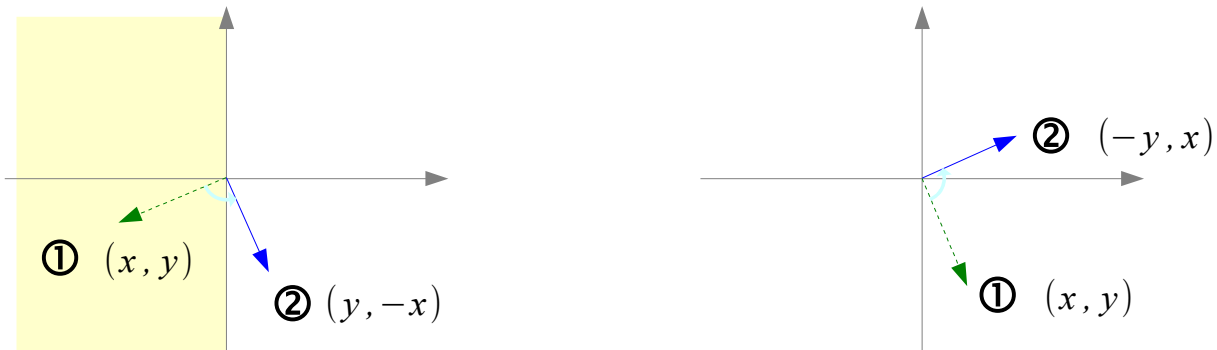
$y_i > 0$
Increases Angle $+\theta$

Initial Rotation $\pm\pi/2$

Positive Phase ($y > 0$) \rightarrow Rotate by -90 degrees



Negative Phase ($y < 0$) \rightarrow Rotate by $+90$ degrees



Resulting Phase \rightarrow $[-90, +90]$

$$x' = -d \cdot y$$

$$y' = +d \cdot x$$

$$z' = z + d \cdot \frac{\pi}{2}$$

$$d = +1 \quad \text{if } y < 0$$

$$d = -1 \quad \text{otherwise}$$

No magnitude change

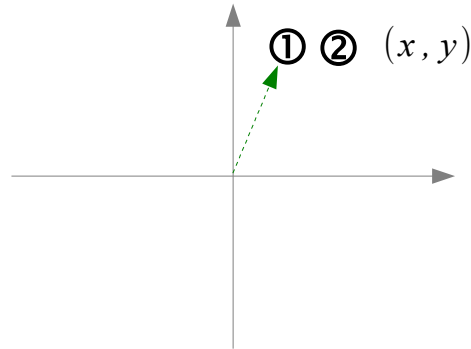
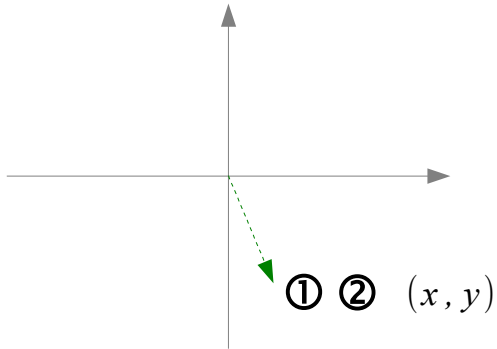
$$x' \leftarrow y$$

$$y' \leftarrow x$$

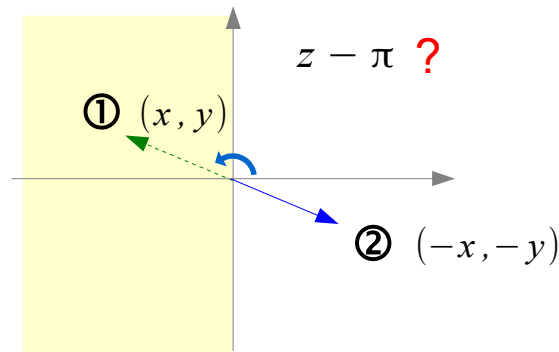
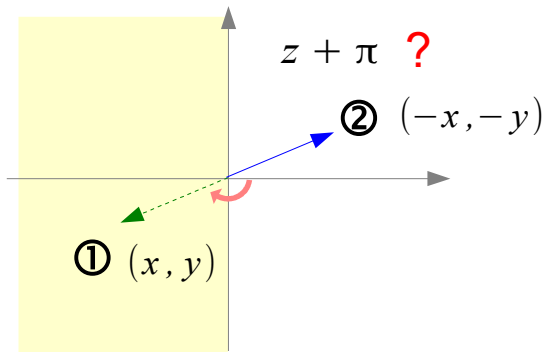
Consistent

Initial Rotation $0, +\pi$

Positive x ($x > 0$) \rightarrow Rotate by 0 degrees



Negative x ($x < 0$) \rightarrow Rotate by $+180$ degrees



Resulting Phase \rightarrow $[-90, +90]$

$$\begin{aligned} x' &= +d \cdot x \\ y' &= +d \cdot y \\ z' &= z \quad \text{if } d = 1 \\ z' &= \pi - z \quad \text{if } d = -1 \end{aligned}$$

$$\begin{aligned} d &= -1 \quad \text{if } x < 0 \\ d &= +1 \quad \text{otherwise} \end{aligned}$$

No magnitude change

$$x' \leftarrow y$$

$$y' \leftarrow x$$

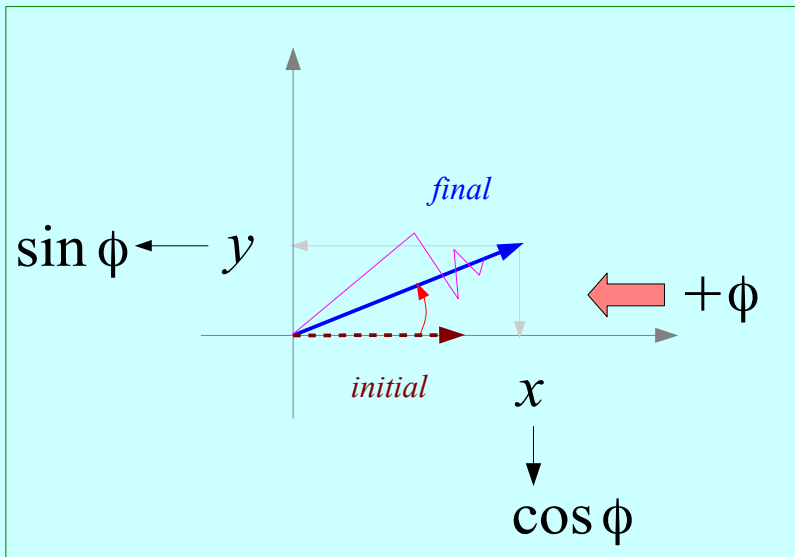
Convenient wiring in FPGA

Application Modes (1)

Rotation Mode

Input angle is given

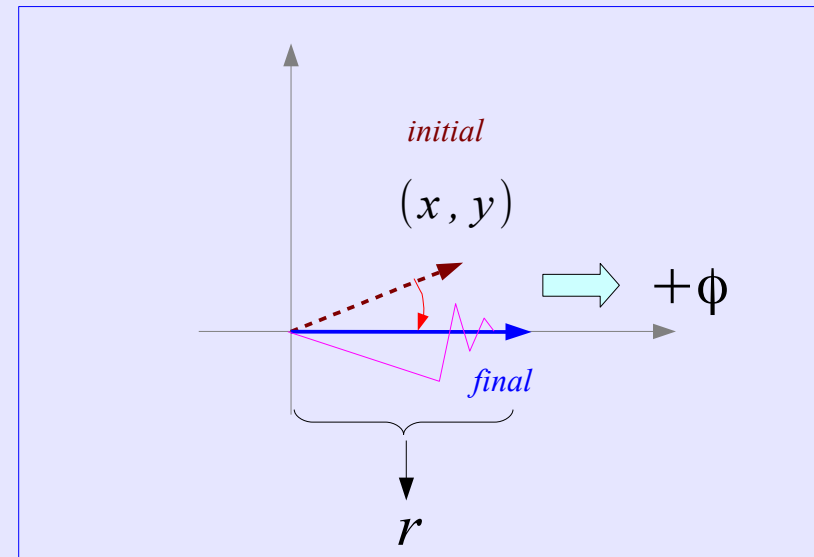
- **sin** and **cos**
- $(r, \theta) \rightarrow (x, y)$
- General vector rotation



Vectoring Mode

Finding the resulting angle

- **\tan^{-1}**
- Vector Magnitude
- $(x, y) \rightarrow (r, \theta)$



Application Modes (2)

- A. **sin & cos**
- B. **$(r, \theta) \rightarrow (x, y)$**
- C. General Vector Rotation
- D. **\tan^{-1}**
- E. Vector Magnitude
- F. **$(x, y) \rightarrow (r, \theta)$**
- G. **\sin^{-1}**
- H. **\cos^{-1}**
- I. Linear Functions
- J. Hyperbolic Functions

A. Sine and Cosine

Rotation Mode

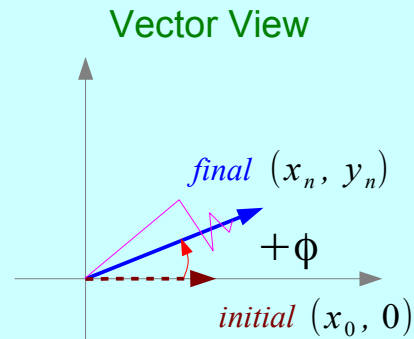
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

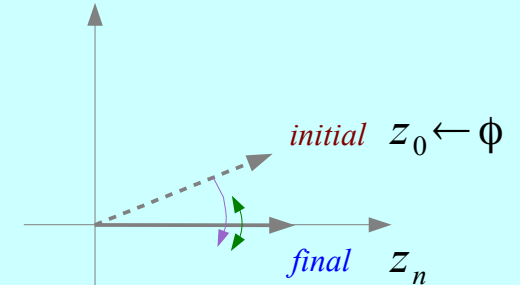
$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle

Accumulator View



Subtract angles at each step

Finding Sine and Cosine

$$(x_0, 0) \rightarrow (x_n, y_n)$$

$$x_n = A_n \cdot x_0 \cos z_0$$

$$y_n = A_n \cdot x_0 \sin z_0$$

Unscaled Sine and Cosine

$$x_0 \leftarrow \frac{1}{A_n} = 0.6073$$

$$x_n = \cos z_0$$

$$y_n = \sin z_0$$

Modulated Sine and Cosine

$$x_0 \leftarrow \left\{ \prod_{i=1}^n K_i \right\} \cdot x_0 = 0.6073 \cdot x_0$$

$$x_n = x_0 \cdot \cos z_0$$

$$y_n = x_0 \cdot \sin z_0$$

CORDIC Gain : *growing in magnitude*

$$A_n = \prod_{i=1}^n \frac{1}{K_i} = \prod_{i=1}^n \sqrt{1 + 2^{-2i}} \rightarrow 1.647$$

LUT \rightarrow a pair of MULT

CORDIC \rightarrow rotation operations

Single MULT

B. Polar to Rectangular

Rotation Mode

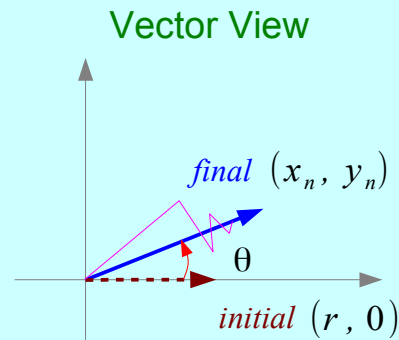
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

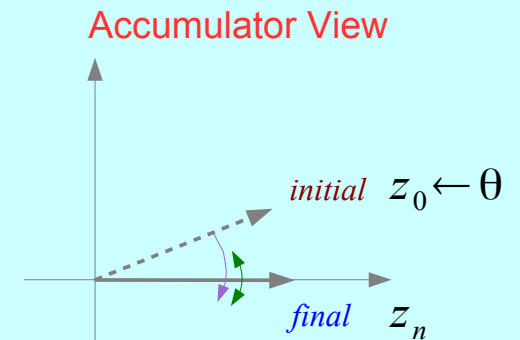
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle



Subtract angles at each step

Finding Sine and Cosine

$$(x_0, 0) \rightarrow (x_n, y_n)$$

$$x_n = A_n \cdot x_0 \cos z_0$$

$$y_n = A_n \cdot x_0 \sin z_0$$

$$x_0 \leftarrow r, \quad z_0 \leftarrow \theta$$

$$(r, 0) \rightarrow (x_n, y_n)$$

$$x_n = A_n r \cos \theta$$

$$y_n = A_n r \sin \theta$$

$$x_0 \leftarrow r \cdot \frac{1}{A_n}, \quad z_0 \leftarrow \theta$$

$$\left(\frac{r}{A_n}, 0\right) \rightarrow (x_n, y_n)$$

$$x_n = r \cos \theta$$

$$y_n = r \sin \theta$$

CORDIC Gain : *growing in magnitude*

$$A_n = \prod_{i=1}^n \frac{1}{K_i} = \prod_{i=1}^n \sqrt{1 + 2^{-2i}} \rightarrow 1.647$$

C. General Vector Rotation

Rotation Mode

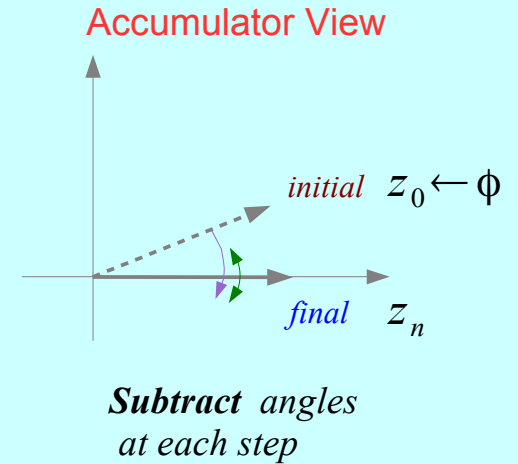
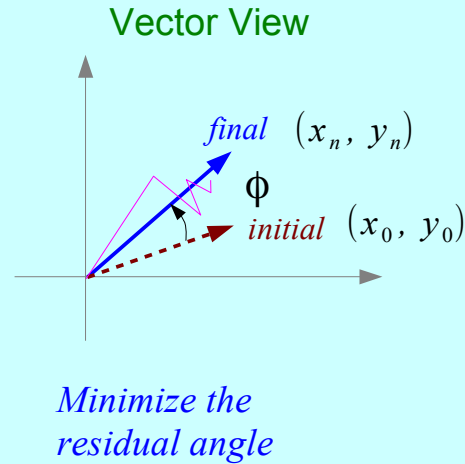
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Motion Correction and Control System

$$\begin{bmatrix} x_n \\ y_n \end{bmatrix} = A_n \cdot \begin{bmatrix} \cos z_0 & -\sin z_0 \\ \sin z_0 & \cos z_0 \end{bmatrix} \begin{bmatrix} x_0 \\ y_0 \end{bmatrix}$$

* n-dim rotation
→ tree architecture

Unscaled Rotation

$$\begin{bmatrix} x_n \\ y_n \end{bmatrix} = A_n \cdot \begin{bmatrix} \cos z_0 & -\sin z_0 \\ \sin z_0 & \cos z_0 \end{bmatrix} \begin{bmatrix} \frac{x_0}{A_n} \\ \frac{y_0}{A_n} \end{bmatrix} \begin{matrix} \rightarrow \text{A pair of} \\ \rightarrow \text{MULT} \end{matrix} \Rightarrow \begin{bmatrix} x_n \\ y_n \end{bmatrix} = \begin{bmatrix} \cos z_0 & -\sin z_0 \\ \sin z_0 & \cos z_0 \end{bmatrix} \begin{bmatrix} x_0 \\ y_0 \end{bmatrix}$$

D. Arctangent

Vectoring Mode

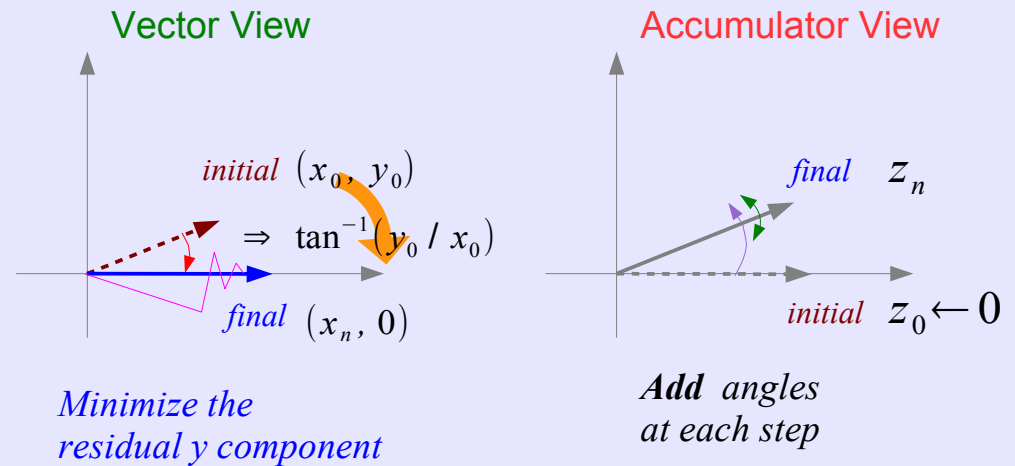
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Input

$$(x_0, y_0) \rightarrow \text{ratio } \frac{y_0}{x_0}$$

$$(0, y_0) \rightarrow \text{ratio } \pm\infty$$

Output

Angle Accumulator Value

→ CORDIC gain does not affect

$$x_n = z_0 + \tan^{-1}(y_0/x_0)$$

E. Vector Magnitude

Vectoring Mode

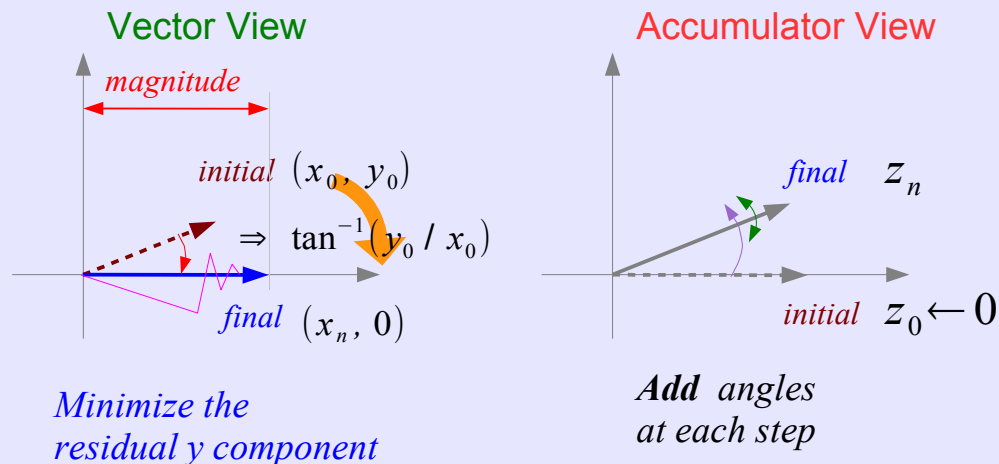
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



The magnitude:

- byproduct of computing arctangent
- the result vector is aligned with x-axis
- the x component of the result vector
- increased by CORDIC gain
- can be scaled by the processor gain
- one MULT hardware cost

$$x_n = A_n \sqrt{x_0^2 + y_0^2}$$

The accuracy of the magnitude result

- Improves by 2 bits for each iteration performed

F. Cartesian to Polar Transformation

Vectoring Mode

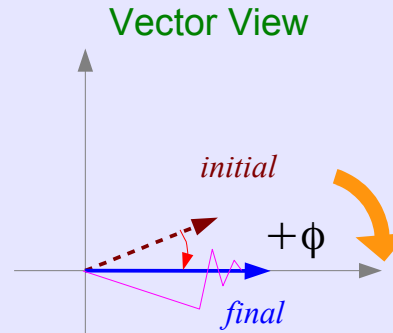
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

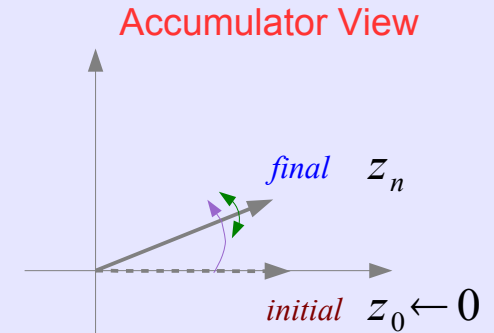
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

input vector (x, y)

magnitude $r = \sqrt{x^2 + y^2}$



$$x_n = A_n \sqrt{x_0^2 + y_0^2}$$

phase angle $\phi = \tan^{-1}(y/x)$



$$z_n = z_0 + \tan^{-1}(y_0/x_0)$$

G. ArcSine (1)

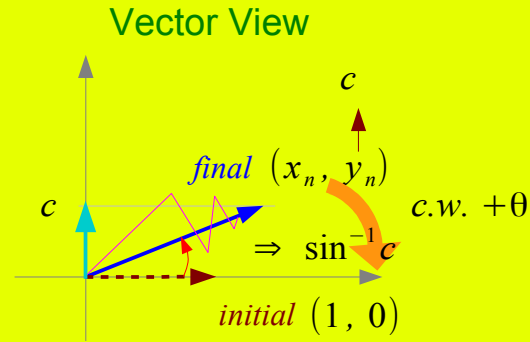
Exploit Vector Mode HW

$$z_n \rightarrow z_0 + \sin^{-1}\left(\frac{c}{A_n \cdot x_0}\right)$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

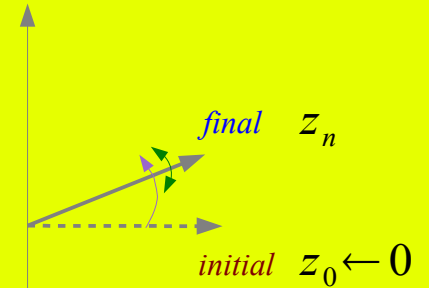
$$d_i = +1 \quad \text{if } y_i < c$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component

Accumulator View



Add angles at each step

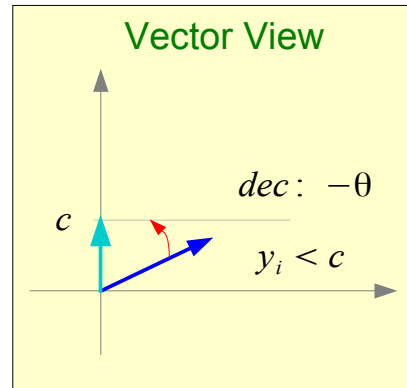
$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

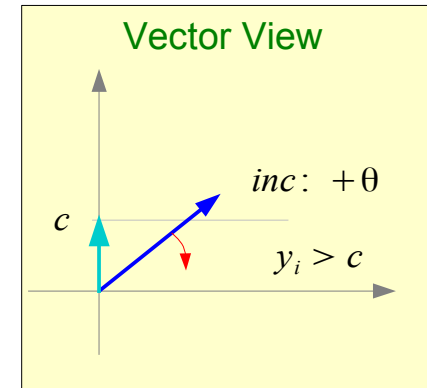
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < c$$

$$d_i = -1 \quad \text{otherwise}$$



$y_i < c$ Dec Angle
Add (-) Angle



$y_i > c$ Inc Angle
Add (+) Angle

G. ArcSine (2)

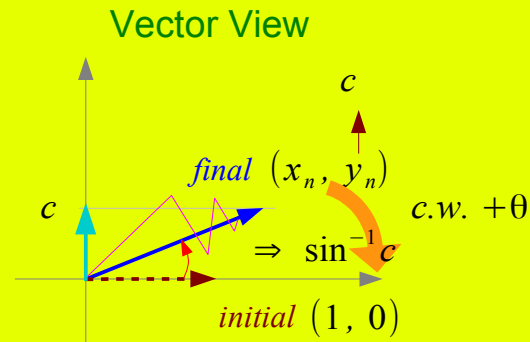
Exploit Vector Mode HW

$$z_n \rightarrow z_0 + \sin^{-1}\left(\frac{c}{A_n \cdot x_0}\right)$$

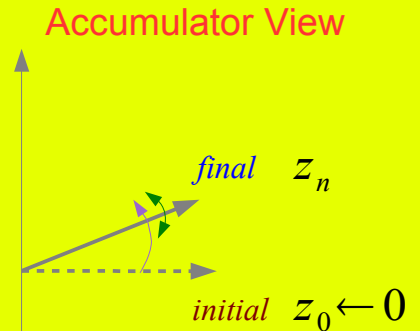
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < c$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < c$$

$$d_i = -1 \quad \text{otherwise}$$

$$x_n = \sqrt{(A_n \cdot x_0)^2 - c^2}$$

$$y_n = c$$

$$z_n = z_0 + \sin^{-1}\left(\frac{c}{A_n \cdot x_0}\right)$$

$$A_n = \prod_{i=1}^n \sqrt{1 + 2^{-2i}}$$

H. Arccosine (1)

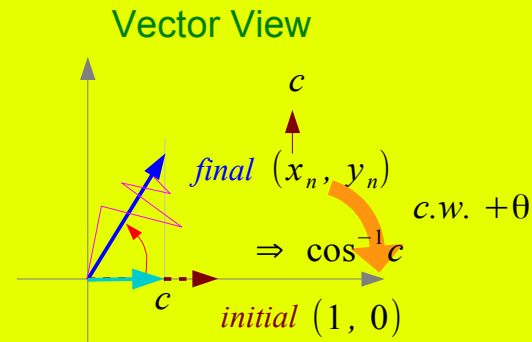
Exploit Vector Mode HW

$$z_n \rightarrow z_0 + \sin^{-1}\left(\frac{c}{A_n \cdot x_0}\right)$$

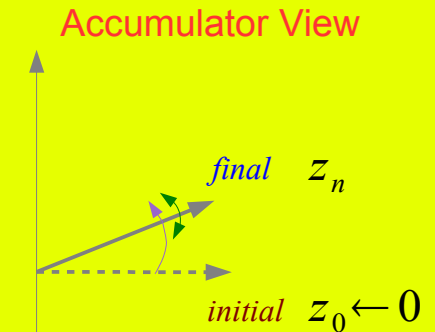
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < c$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual x component



Add angles at each step

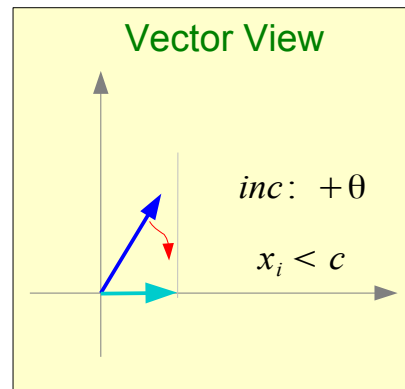
$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

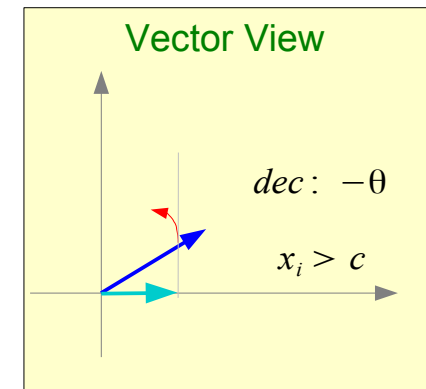
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } x_i > c$$

$$d_i = -1 \quad \text{otherwise}$$



$x_i < c$ Inc Angle
Add (+) Angle



$x_i > c$ Dec Angle
Add (-) Angle

H. Arccosine (1)

Exploit Vector Mode HW

$$z_n \rightarrow z_0 + \sin^{-1}\left(\frac{c}{A_n \cdot x_0}\right)$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < c$$

$$d_i = -1 \quad \text{otherwise}$$

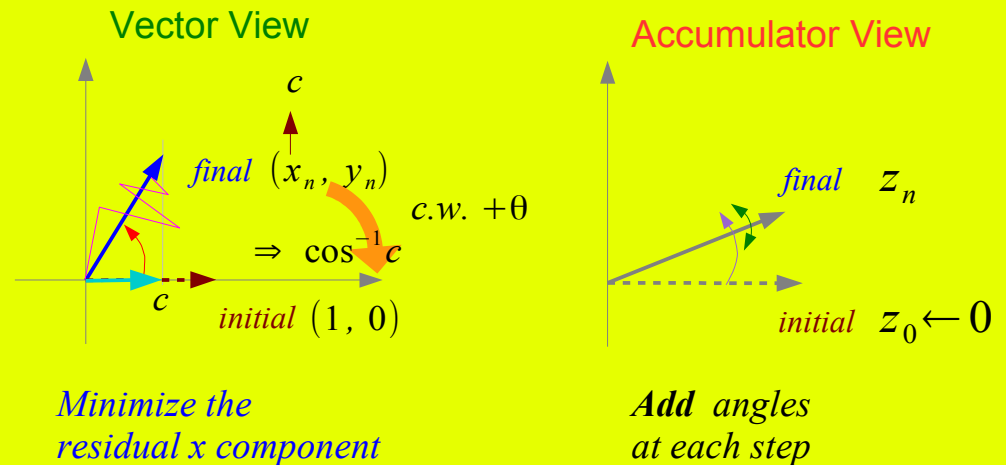
$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } x_i > c$$

$$d_i = -1 \quad \text{otherwise}$$



$$y_n = \sqrt{(A_n \cdot y_0)^2 - c^2}$$

$$x_n = c$$

$$z_n = z_0 + \cos^{-1}\left(\frac{c}{A_n \cdot y_0}\right)$$

$$A_n = \prod_{i=1}^n \sqrt{1 + 2^{-2i}}$$

I. Linear Functions (1)

Rotation Mode

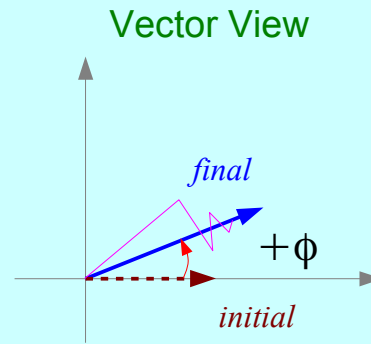
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

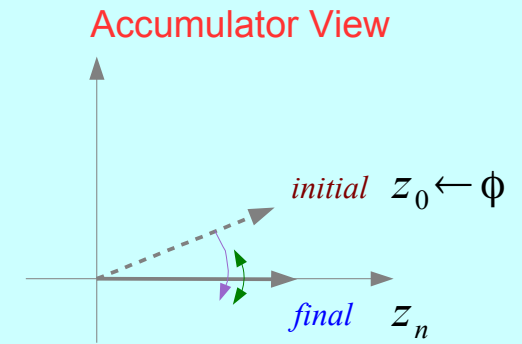
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle



Subtract angles at each step

$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$x_{i+1} = x_i - \mathbf{0} \cdot y_i \cdot d_i \cdot 2^{-i} = x_i$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot (2^{-i})$$

$$x_n = A_n \begin{bmatrix} x_0 \cos z_0 - y_0 \sin z_0 \\ y_0 \cos z_0 + x_0 \sin z_0 \end{bmatrix}$$

$$y_n = A_n \begin{bmatrix} x_0 \cos z_0 - y_0 \sin z_0 \\ y_0 \cos z_0 + x_0 \sin z_0 \end{bmatrix}$$

$$z_n = 0$$

$$x_n = x_0$$

$$y_n = y_0 + x_0 z_0$$

$$z_n = 0$$

I. Linear Functions (2)

Vectoring Mode

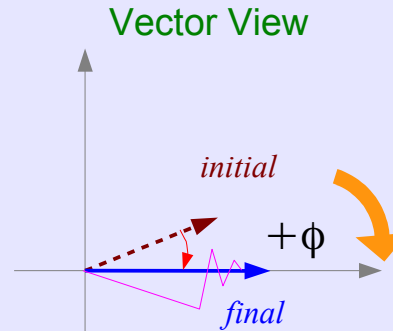
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

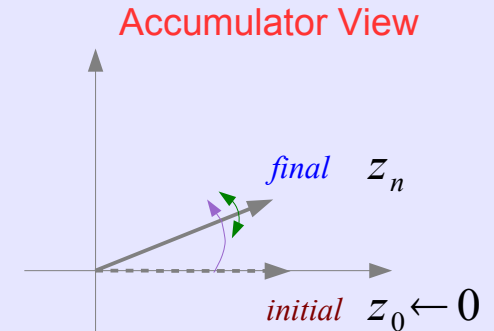
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$x_{i+1} = x_i - \mathbf{0} \cdot y_i \cdot d_i \cdot 2^{-i} = x_i$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot (2^{-i})$$

$$x_n = A_n \sqrt{x_0^2 + y_0^2}$$

$$y_n = 0$$

$$z_n = z_0 + \tan^{-1}(y_0/x_0)$$

$$x_n = x_0$$

$$y_n = 0$$

$$z_n = z_0 - (y_0/x_0)$$

J. Hyperbolic Functions (1)

Rotation Mode

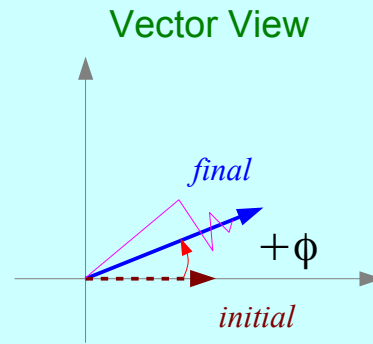
$$z_0 \leftarrow \phi \quad (\text{desired angle})$$

$$z_n \rightarrow 0$$

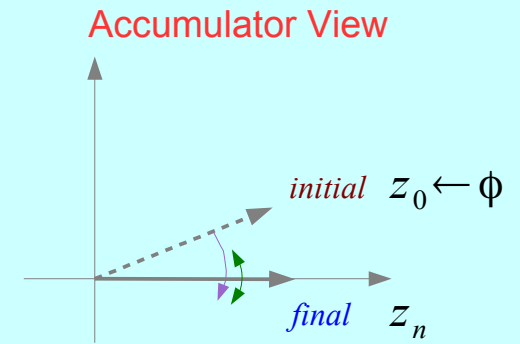
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = -1 \quad \text{if } z_i < 0$$

$$d_i = +1 \quad \text{otherwise}$$



Minimize the residual angle



Subtract angles at each step

$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$x_{i+1} = x_i + y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \mathbf{tanh}^{-1}(2^{-i})$$

$$x_n = A_n [x_0 \cos z_0 - y_0 \sin z_0]$$

$$y_n = A_n [y_0 \cos z_0 + x_0 \sin z_0]$$

$$z_n = 0$$

$$x_n = A_n [x_0 \mathbf{cosh} z_0 - y_0 \mathbf{sinh} z_0]$$

$$y_n = A_n [y_0 \mathbf{cosh} z_0 + x_0 \mathbf{sinh} z_0]$$

$$z_n = 0$$

J. Hyperbolic Functions (1)

Vectoring Mode

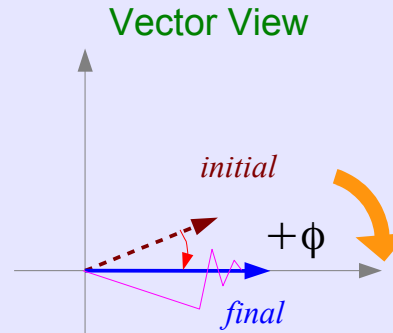
$$z_0 \leftarrow 0$$

$$z_n \rightarrow z_0 + \tan^{-1}(y_0/x_0)$$

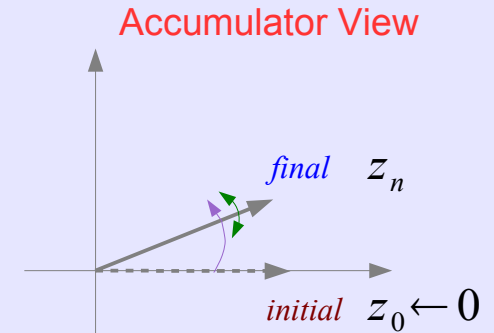
$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$d_i = +1 \quad \text{if } y_i < 0$$

$$d_i = -1 \quad \text{otherwise}$$



Minimize the residual y component



Add angles at each step

$$x_{i+1} = x_i - y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \tan^{-1}(2^{-i})$$

$$x_{i+1} = x_i + y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot \mathbf{tanh}^{-1}(2^{-i})$$

$$x_n = A_n \sqrt{x_0^2 + y_0^2}$$

$$y_n = 0$$

$$z_n = z_0 + \tan^{-1}(y_0/x_0)$$

$$x_n = A_n \sqrt{x_0^2 - y_0^2}$$

$$y_n = 0$$

$$z_n = z_0 + \mathbf{tanh}^{-1}(y_0/x_0)$$

Unified CORDIC Iteration Eq

$$x_{i+1} = x_i - m \cdot y_i \cdot d_i \cdot 2^{-i}$$

$$y_{i+1} = y_i + x_i \cdot d_i \cdot 2^{-i}$$

$$z_{i+1} = z_i - d_i \cdot e_i$$

$$m = 1 \Rightarrow e_i = \tan^{-1}(2^{-i})$$

$$m = 0 \Rightarrow e_i = (2^{-i})$$

$$m = -1 \Rightarrow e_i = \tanh^{-1}(2^{-i})$$

$$\tan \alpha = \frac{\sin \alpha}{\cos \alpha}$$

$$\tanh \alpha = \frac{\sinh \alpha}{\cosh \alpha}$$

$$\exp \alpha = \sinh \alpha + \cosh \alpha$$

$$\ln \alpha = 2 \tanh^{-1}(y/x)$$

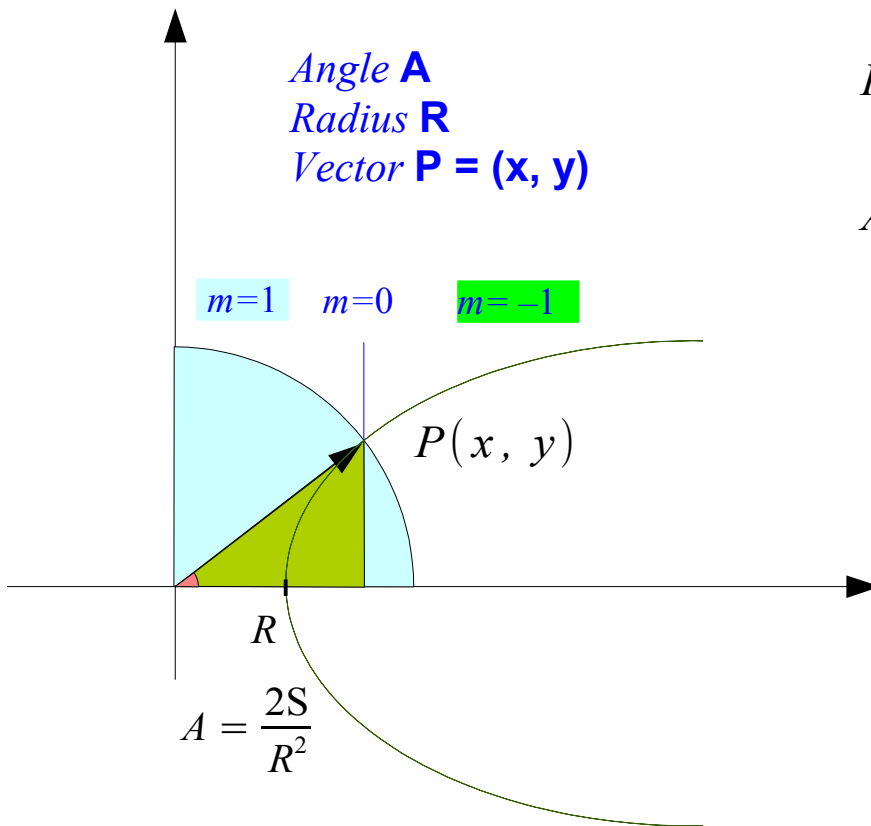
$$x = \alpha + 1$$

$$y = \alpha - 1$$

$$(\alpha)^{1/2} = (x^2 - y^2)^{1/2}$$

$$x = \alpha + 1/4$$

$$y = \alpha - 1/4$$

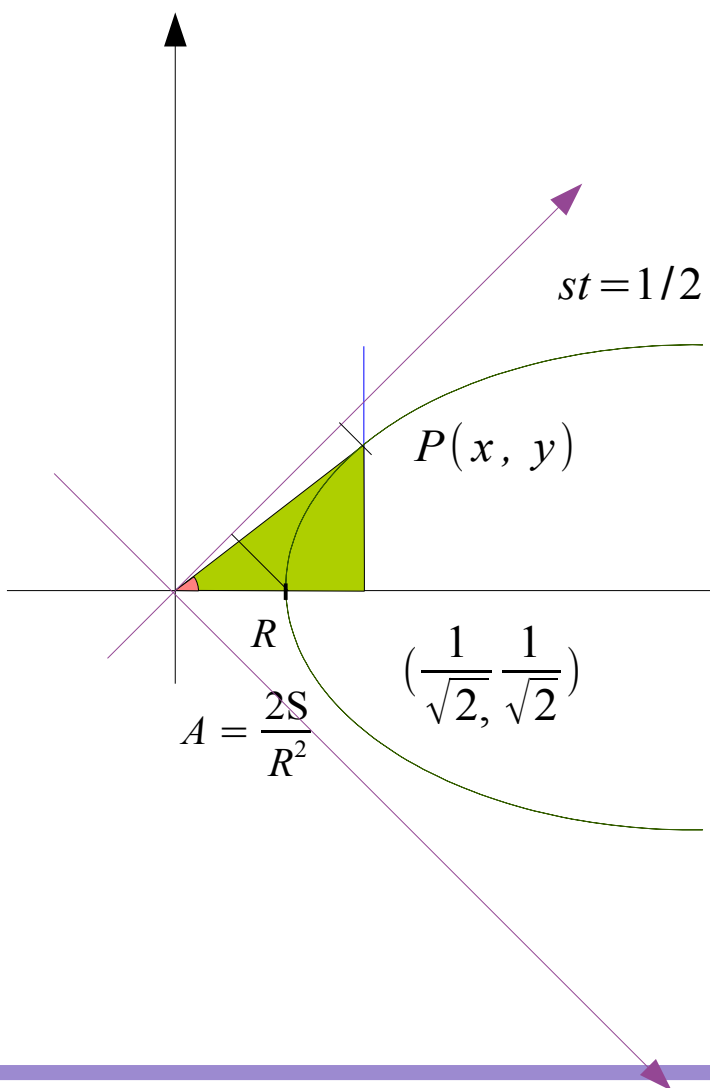


$$R = (x^2 + y^2)^{1/2}$$

$$A = \tan^{-1}\left(\frac{y}{x}\right)$$

$$R = (x^2 - y^2)^{1/2}$$

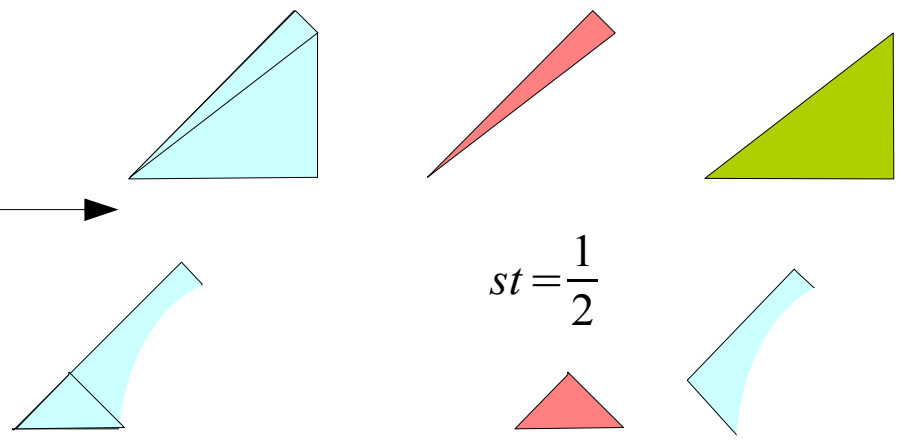
$$A = \tan^{-1}\left(\frac{y}{x}\right)$$

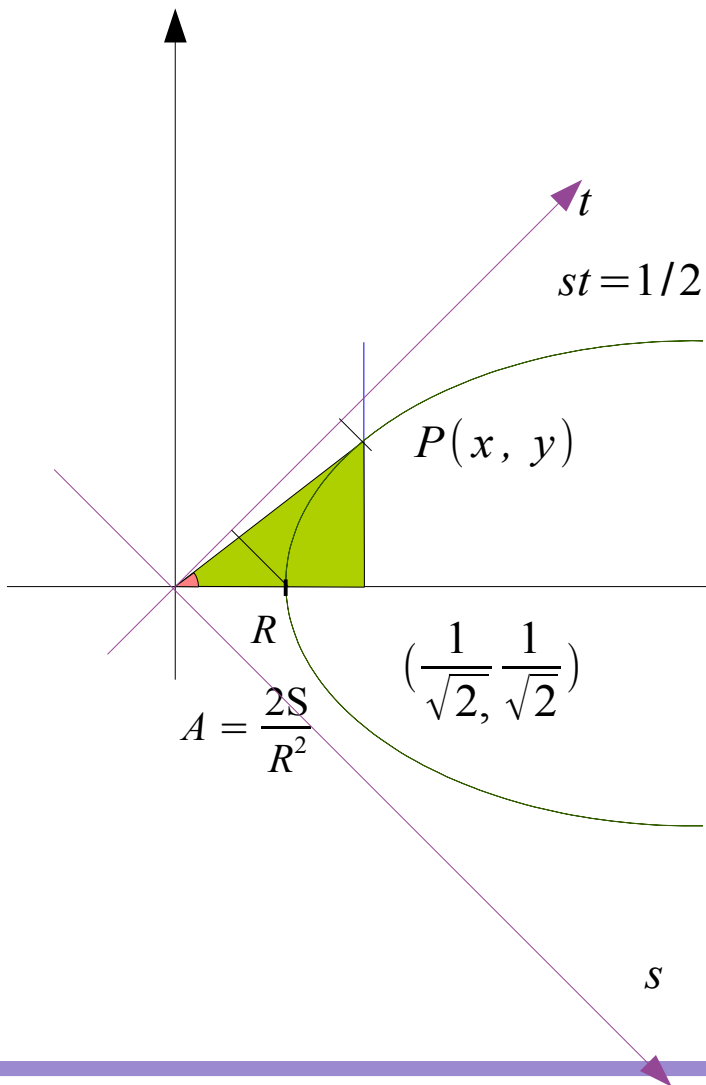


$$x - y = s\sqrt{2}$$

$$x + y = t\sqrt{2}$$

$$st = \frac{1}{2}$$



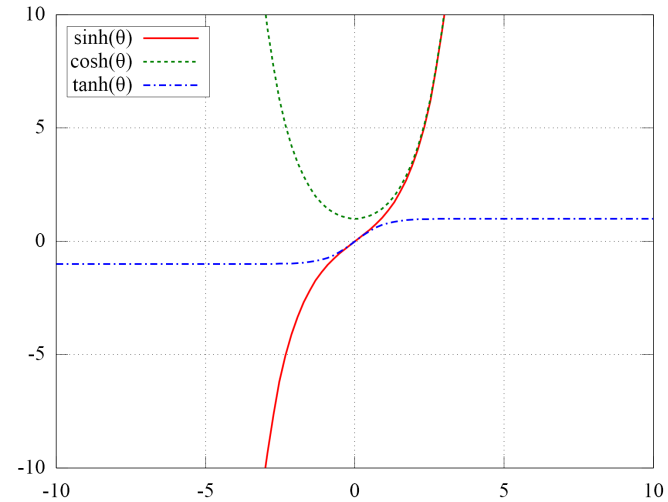
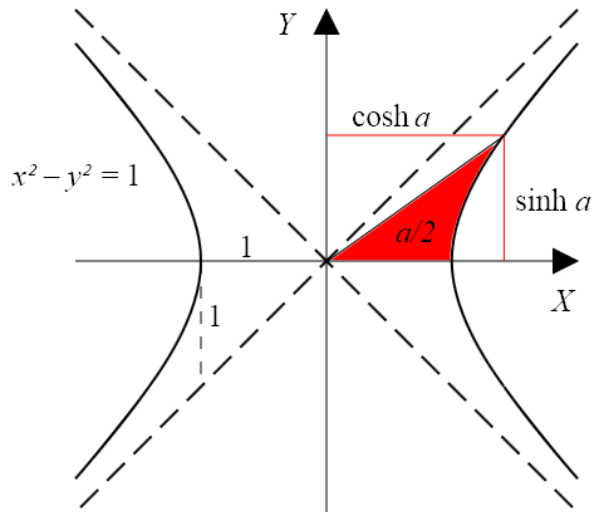


$$x - y = s\sqrt{2}$$

$$x + y = t\sqrt{2}$$

$$st = \frac{1}{2}$$

$$2A = 2 \int_{\frac{1}{\sqrt{2}}}^{\frac{(x+y)}{\sqrt{2}}} \frac{ds}{2s} = \ln(x+y) = \ln(x \pm \sqrt{x^2 - 1})$$



$$x^2 - y^2 = 1 \quad (\sinh \alpha, \cosh \alpha)$$

$$\cosh^2 \alpha - \sinh^2 \alpha = 1$$

$$\frac{1}{4}(e^\alpha + e^{-\alpha})^2 - \frac{1}{4}(e^\alpha - e^{-\alpha})^2 = 1$$

$$\sinh \alpha = \frac{1}{2}(e^\alpha - e^{-\alpha})$$

$$\cosh \alpha = \frac{1}{2}(e^\alpha + e^{-\alpha})$$

$$\tanh \alpha = \frac{(e^\alpha - e^{-\alpha})}{(e^\alpha + e^{-\alpha})}$$

$$e^{+ix} = \cos x + i \sin x$$

$$e^{-ix} = \cos x - i \sin x$$

$$\cos x = \frac{1}{2}(e^{+ix} + e^{-ix}) \Rightarrow \mathbf{\cosh ix}$$

$$i \sin x = \frac{1}{2}(e^{+ix} - e^{-ix}) \Rightarrow \mathbf{i \sinh ix}$$

$$i \frac{\sin x}{\cos x} = \frac{(e^{+ix} - e^{-ix})}{(e^{+ix} + e^{-ix})} \Rightarrow \mathbf{i \tanh ix}$$

$$e^{+ix} = \mathbf{\cosh ix + \sinh ix}$$

$$e^{-ix} = \mathbf{\cosh ix - \sinh ix}$$

References

- [1] <http://en.wikipedia.org/>
- [2] CORDIC FAQ, www.dspguru.com
- [3] R. Andraka, A survey of CORDIC algorithms for FPGA based computers
- [4] J. S. Walther, A Unified Algorithm for Elementary Functions