**Design Guide: TIDA-010022**

**People counting and tracking using mmWave radar sensor with sub-1 GHz reference design**

**Description**

This design demonstrates the use of the IWR6843 device, a single-chip, mmWave radar sensor from TI with integrated DSP, for an indoor and outdoor people-counting application along with sub-1 GHz wireless communication. This reference design uses the MMWAVEICBOOST and IWR6843ISK evaluation modules (EVMs) together with the LAUNCHXL-CC1352R1 wireless MCU LaunchPad™. This solution is shown to localize people out to 6 m (short-range configuration) and 14 m (long-range configuration).

**Features**

- Contains demonstration hardware and software to use the IWR6843 device and mmWave radar sensor for people counting and tracking
- Long-range, low power sub-1 GHz wireless connectivity using the CC1352 device
- IEEE 802.15.4e or IEEE 802.15.4g stack with collector and sensor application
- mmWave technology provides the range, velocity, and angle information – ideal for environmental effects
- Azimuth field of view of 120° across a distance of 6 m, that can extend to 14 m with different chip configuration
- Examples of implementation of static clutter and group-tracking algorithms

**Resources**

TIDA-010022 Design Folder
IWR6843 Product Folder
CC1352R Product Folder
MMWAVEICBOOST Tool Folder
IWR6843ISK Tool Folder
LAUNCHXL-CC1352R1 Tool Folder

**Applications**

- Occupancy detection
- Motion detector
- Automated doors and gates
- IP network camera
- Smoke and heat detector
- Lighting sensors
People counting and tracking using mmWave radar sensor with sub-1 GHz reference design

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1 System Description

Industrial and building automation security systems can use radar to detect and track humans and other objects. In a security system, mmWave technology provides range, velocity, and angle information that is immune to environmental effects. The CC1352 wireless radio microcontroller provides extended long-range connection in spread-out areas to monitor and track activity with ultra-low power consumption.

Human monitoring has become an important area of exploration, due to its potential for understanding people’s count, activities, intents, and health issues. The ability to continuously and consistently monitor human motion is an important function in numerous applications, including surveillance, control, and analysis. Accuracy and precision play an important role in these applications. While sensors such as passive infra-red (PIR) and time of flight (TOF) are in use, they suffer from limitations in accuracy, false alarms, and environmental changes such as darkness, brightness, and smoke.

Radars allow an accurate measurement of distances, relative velocities of people, and other objects. They are relatively immune to environmental conditions such as the effects of rain, dust, or smoke. Additionally, they can work in complete darkness or in bright daylight. They are therefore useful for building automation applications such as people counting, motion detection, IP network cameras, and safety guards.

Sub-1 GHz wireless radio microcontrollers are becoming a popular choice for many applications worldwide. These devices work on the ISM spectrum bands below 1 GHz, typically in the 769 MHz to 935 MHz, 315 MHz, and the 468 MHz frequency range, and with the emerging IoT market moving into industrial applications, sub-1 GHz wireless radio communication is becoming the standard for these applications due to three main reasons: range, low power consumption, and interference to avoid problems associated with high traffic bands.

This design guide addresses component selection, design theory, and the testing results of this TI Design system. The scope of this design guide gives system designers a head-start in integrating TI’s mmWave sensor and SimpleLink™ multi-band wireless MCU.

The following subsections describe the various blocks within the TI Design system and what characteristics are most critical to best implement the corresponding function.

1.1 Key System Specifications

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<td>mmWave Radar</td>
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<td>3.6 W</td>
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<td>Radar field of view</td>
<td>120° horizontal, 30° vertical</td>
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<td>Radar maximum range</td>
<td>6 m for short range configuration and 14 m for long range configuration</td>
<td>Section 3.2.2.1</td>
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<td>Radar range resolution</td>
<td>4.9 cm for short range configuration and 12 cm for long range configuration</td>
<td>Section 3.2.2.1</td>
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<tr>
<td>Radar maximum velocity</td>
<td>18.64 km/h for short range configuration and 18.9 km/h for long range configuration</td>
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<tr>
<td>Radar velocity resolution</td>
<td>0.297 km/h for both short and long range configuration</td>
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<td>Frame rate</td>
<td>Up to 20 frames per second</td>
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<td>Up to 20 objects</td>
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</tr>
<tr>
<td>Radio transmitter frequency</td>
<td>915 MHz</td>
<td>Section 2.2.3</td>
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<tr>
<td>Radio transmit power</td>
<td>12 dBm</td>
<td>Section 2.2.3</td>
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<td>Radio transmission range</td>
<td>70 m</td>
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<tr>
<td>Network type</td>
<td>Star</td>
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</tr>
</tbody>
</table>
2 System Overview

2.1 Block Diagram

![Figure 1. TIDA-010022 Block Diagram](image)

2.2 Design Considerations

The people counting and tracking using mmWave radar sensor with Sub-1 GHz reference design counts the number of objects within its field of view and sends the data over the air to a collector node.

2.2.1 mmWave Sensor

2.2.1.1 mmWave Sensor People Counting

The implementation of the people-counting application example in the signal-processing chain consists of the following blocks, implemented as DSP code executing on the C674x core in the IWR6843. The tracking module runs on the ARM® Cortex®-R4F processor.

- **Range Processing:**
  - For each antenna, 1D windowing, and 1D fast Fourier transform (FFT)
  - Range processing is interleaved with the active chirp time of the frame

- **Capon beam forming:**
  - Static clutter removal
  - Co-variance matrix generation, inverse-angle spectrum generation, and integration is performed
  - Outputs range-angle heat map

- **CFAR detection algorithm:**
  - Two-pass, constant false-alarm rate
  - First pass cell averaging smallest of CFAR-CASO in the range domain, confirmed by second pass cell averaging smallest of CFAR-CASO in the angle domain, to find detection points.

- **Doppler estimation:**
  - For each detected [range, azimuth] pair from the detection module, estimate the Doppler by filtering the range bin using Capon beam-weights, and then run a peak search over the FFT of the filtered range bin.

- **Tracking:**
  - Perform target localization, and report the results.
  - Output of the tracker is a set of trackable objects with certain properties like position, velocity, physical dimensions, and point density
2.2.1.2 IWR6843 UART Communication

The CC1352 device configures the IWR6843 device via a command line interface (CLI) UART port. After the configuration is completed, the IWR6843 starts sending out radar data continuously back to CC1352 through a separate data UART port. Then, the CC1352 parses the data from the IWR6843 and packetizes and sends the data package over the air to the collector node constantly. Figure 3 is a block diagram of the IWR6843 UART communication.

2.2.1.2.1 IWR6843 Frame Output

The IWR6843 outputs one frame every frame period. The frame has a fixed header, followed by a variable number of segments in tag, length, value (TLV) format. Each TLV has a fixed header, followed by a variable-size payload. Byte order is little endian. Figure 4 illustrates the IWR6843 output frame format.

2.2.1.2.2 IWR6843 Frame Header

The frame header is a fixed size (52 bytes) and has the following structure (see Figure 5 using MATLAB® notation, with name, type, and length in bytes). The header is designed to self-describe the content, and allow the user application to operate in a lossy environment.
frameHeaderStructType = struct(...
    'sync', {'uint64', 8}, ... % Sync Pattern
    'version', {'uint32', 4}, ... % mmWaveSDK version
    'platform', {'uint32', 4}, ... % 0xA1642 or 0xA1443
    'timestamp', {'uint32', 4}, ... % 600MHz free running clocks
    'packetLength', {'uint32', 4}, ... % In bytes, including header
    'frameNumber', {'uint32', 4}, ... % Starting from 1
    'subframeNumber', {'uint32', 4}, ...
    'chirpMargin', {'uint32', 4}, ... % Chirp Processing margin, in us
    'frameMargin', {'uint32', 4}, ... % Frame Processing margin, in us
    'uartSentTime', {'uint32', 4}, ... % Time spent to send data, in us
    'trackProcessTime', {'uint32', 4}, ... % Tracking Processing time, in us
    'numTLVs', {'uint16', 2}, ... % Number of TLVs in thins frame
    'checksum', {'uint16', 2}); % Header checksum

Figure 5. IWR6843 Frame Header

2.2.1.2.3 TLV Elements

Each TLV has a fixed header (8 bytes) followed by a TLV-specific payload (see Figure 6).

tlvHeaderStruct = struct(...
    'type', {'uint32', 4}, ... % TLV object Type
    'length', {'uint32', 4}); % TLV object Length, in bytes, including TLV header

Figure 6. TLV Header

Three TLVs are supported at this time, as follows:

• Point Cloud TLV
  – Type = POINT_CLOUD_2D
  – Length = sizeof (tlvHeaderStruct) + sizeof (pointStruct2D) × numberOfPoints

% Point Cloud TLV object consists of an array of points.
% Each point has a structure defined below

pointStruct2D = struct(...
    'range', {'float', 4}, ... % Range, in m
    'azimuth', {'float', 4}, ... % Angle, in rad
    'doppler', {'float', 4}, ... % Doppler, in m/s
    'snr', {'float', 4}); % SNR, ratio

Figure 7. Point Cloud TLV

• Target List TLV
  – Type = TARGET_LIST
  – Length = sizeof (tlvHeaderStruct) + sizeof (targetStruct) × numberOfTargets
% Target List TLV object consists of an array of targets. 
% Each target has a structure define below

targetStruct2D = struct(...
  'tid',            { 'uint32', 4}, ... % Track ID
  'posX',           { 'float', 4}, ... % Target position in X dimension, m
  'posY',           { 'float', 4}, ... % Target position in Y dimension, m
  'velX',           { 'float', 4}, ... % Target velocity in X dimension, m/s
  'velY',           { 'float', 4}, ... % Target velocity in Y dimension, m/s
  'accX',           { 'float', 4}, ... % Target acceleration in X dimension, m/s
  'accY',           { 'float', 4}, ... % Target acceleration in Y dimension, m/s
  'EC',             { 'float', 9*4}, ... % Tracking error covariance matrix, [3x3], in
  range/angle/doppler coordinates
  'G',              { 'float', 4});    % Gating function gain

Figure 8. Target List TLV

NOTE: The target index TLV received in the N-th frame indices the point cloud in (N–1)th frame.

• Target Index TLV
  – Type = TARGET_INDEX
  – Length = sizeof(tlvHeaderStruct) + numberOfPoints
  – Payload is a byte array, each byte represents a tracking ID

NOTE: The track ID is a byte. Values 0 to 249 are supported. Values 250 to 255 are reserved.

2.2.2 Power Supply Design

To design a proper power supply for the system, consider the following specs:
1. The IWR6843 chip requires multiple voltage rails: 3.3 V, 1.8 V, 1.24 V, 1.0 V
2. The CC1352 chip requires a 3.3-V rail
3. The main power supply to the sensor node is 5 V

In this design, the LP8770 PMIC on the IWR6843ISK board is used to generate the voltage rails for the IWR6843. The IWR6843ISK receives 3.3 V from the MMWAVEICBOOST board.

The CC1352 device used in the sensor node is powered directly from the 3.3-V rail (BRD_3V3) generated by the LM53635-Q1 DC-DC converter on the MMWAVEICBOOST board. This 3.3 V rail provides power to various components (muxes, serial interfaces, debug, etc.) on the MMWAVEICBOOST board, including the IWR6843ISK board.
2.2.3 Wireless Network Design

This design leverages TI's SimpleLink TI-15.4 Stack to implement a star network. The TI-15.4 Stack implements the standard IEEE 802.15.4e, IEEE 802.15.4g specification and is designed to run on SimpleLink CC1352 ultra-low-power MCUs. The TI 15.4 Stack supports different modes including frequency hopping where network devices hop on different frequencies, beacon mode where the network coordinator transmits periodic beacons to indicate its presence, and non-beacon mode where the coordinator does not send out periodic beacons.

The network consists of a central device, or collector, and one or more sensor nodes. The collector performs the functions of a network coordinator (starts the network, allows devices to join the network) and receives data from the sensor nodes. The collector then sends periodic tracking request messages (to which it expects tracking response messages) to determine whether or not the sensor nodes are alive in the network.

Sensor nodes join the network started by the collector. They send sensor data reports to the collector and respond to the tracking messages sent by the collector. The sensor nodes also poll for messages from the collector allowing for two-way communication.

This TI Design together with a CC1352 LaunchPad implements the function of the sensor node and collector node. The TI-15.4 Stack is configured for operation in the 915-MHz frequency band (frequency hopping disabled), non-beacon mode enabled, and transmit power set to 12 dBm.

2.2.4 CC1352 Software Design

The collector and sensor software used in this TI design is a modified version of the collector and sensor example code provided with the TI 15.4 Stack. The TI 15.4 Stack and example codes run as state machines waiting for events. To make these example codes work, two modifications were necessary: A new event was added to the collector and sensor examples and added an additional task running in parallel in charge of triggering said event. The new event is triggered when new mmWave data is received from the mmWave. The following section provides is a description of the event and task.
2.2.4.1 Collector Node

Figure 9 illustrates the collector node software flowchart.

![Figure 9. Collector Node Software Flowchart](image)

2.2.4.2 Sensor Node

Figure 10 shows the sensor node software flowchart.

![Figure 10. Sensor Node Software Flowchart](image)
Each sensor packet includes 4 bytes of the frame number, 4 bytes of the number of objects detected, and 12 bytes of tracking information for each object.

The tracking information for each object is 12 bytes which include 4 bytes track ID, 4 bytes target position in the X dimension, and 4 bytes target position in the Y dimension.

```c
/*!
 * mmWave Object Field
 */
typedef struct _Smsgs_objtrackingfield_t
{
    uint32_t tid;
    uint32_t posx;
    uint32_t posy;
} Smsgs_objtrackingfield_t;

/*!
 * mmWave Sensor Field
 */
typedef struct _Smsgs_mmwavesensorfield_t
{
    /*! mmWave frame number */
    uint32_t frame_number;

    /*! Number of objects detected */
    uint16_t num_objs;

    /*! Tracking information for each object */
    Smsgs_objtrackingfield_t objInfo[SMSGS_SENSOR_MMWAVE_MAX_OBJ];
} Smsgs_mmwaveSensorField_t;
```

### 2.2.4.3 mmWave Sensor Configuration Command List Modification

The short range configuration is used by default in this design. Also lowpower and pointCloudEn commands are changed compared to the default command list:

1. Changed "lowpower 0 1\r" to "lowpower 0 0\r" which disables the low power mode since ES1.0 does not use low power mode

2. Added additional command "pointCloudEn 0\r" to disable the point cloud to reduce the burden of the CC1352 device by providing a smaller frame for it to read

```c
const char *CommandList[] = {
    "dfeDataOutputMode 1\r",
    "channelCfg 15 5 0\r",
    "adcCfg 2 1\r",
    "adcbufCfg 0 1 1 1\r",
    "profileCfg 0 60.6 30 10 62 0 0 53 1 128 2500 0 0 30\r",
    "chirpCfg 0 0 0 0 0 0 0 1\r",
    "chirpCfg 1 1 0 0 0 0 0 4\r",
    "frameCfg 0 1 128 0 50 1 0\r",
    "lowPower 0 1\r",
    "guiMonitor 1 1 0 0\r",
    "cfarCfg 6 4 4 4 4 16 16 4 4 50 62 0\r",
    "doaCfg 600 1875 30 1 1 0\r",
    "SceneryParam -6 6 0.5 6\r",
    "GatingParam 4 3 2 0\r",
    "StateParam 10 5 100 100 5\r",
    "AllocationParam 250 250 0.25 10 1 2\r",
    "AccelerationParam 1 1 1\r",
    "PointCloudEn 0\r",
    "trackingCfg 1 2 250 20 52 82 50 90\r",
    "sensorStart\r"
};
```
2.3 **Highlighted Products**

The TIDA-010022 design features the following devices and evaluation platforms (EVMs):

1. IWR6843: Single-chip 60- to 64-GHz mmWave sensor
2. CC1352: SimpleLink high-performance dual-band wireless MCU
3. IWR6843ISK and MMWAVEICBOOST: mmWave EVMs
4. LAUNCHXL-CC1352R1: SimpleLink™ Multi-Band CC1352R Wireless MCU LaunchPad™ Development Kit

For more information on these products, see their data sheet or product folders on www.ti.com.

2.3.1 **IWR6843: Single-Chip 60- to 64-GHz mmWave Sensor**

The IWR1642 device includes the entire Millimeter Wave blocks and analog baseband signal chain for two transmitters and four receivers, as well as a customer-programmable MCU and DSP. The IWR1642 handles all people counting and tracking functions.

In this reference design the IWR1642 device is paired with a CC1352R SimpleLink dual-band wireless MCU to enable wireless communication of people counting and tracking data.

![Figure 11. IWR6843 Block Diagram](image)

*Up to 512KB of Radar Data Memory can be switched to the Master R4F if required

2.3.2 **CC1352R: SimpleLink™ High-Performance Dual-Band Wireless MCU**

The CC1352R device is a multiprotocol Sub-1 and 2.4-GHz wireless MCU targeting Wireless M-Bus, IEEE 802.15.4g, IPv6-enabled smart objects (6LoWPAN), Thread, Zigbee®, KNX RF, Wi-SUN®, Bluetooth® 5 Low Energy, and proprietary systems.
The CC1352R device is a member of the CC26xx and CC13xx family of cost-effective, ultra-low power, 2.4-GHz and Sub-1 GHz RF devices. Very low active RF and microcontroller (MCU) current, in addition to sub-μA sleep current with up to 80KB of RAM retention, provide excellent battery lifetime and allow operation on small coin-cell batteries and in energy-harvesting applications.

The CC1352R device combines a flexible, very low-power RF transceiver with a powerful 48-MHz Arm® Cortex®-M4F CPU in a platform supporting multiple physical layers and RF standards. A dedicated Radio Controller (Arm® Cortex®-M0) handles low-level RF protocol commands that are stored in ROM or RAM, thus ensuring ultra-low power and great flexibility. The low power consumption of the CC1352R device does not come at the expense of RF performance; the CC1352R device has excellent sensitivity and robustness (selectivity and blocking) performance.

The CC1352R device is a highly integrated, true single-chip solution incorporating a complete RF system and an on-chip DC/DC converter.

The CC1352R device is part of the SimpleLink™ microcontroller (MCU) platform, which consists of Wi-Fi®, Bluetooth® Low Energy, Thread, Zigbee, Sub-1 GHz MCUs, and host MCUs, which all share a common, easy-to-use development environment with a single core software development kit (SDK) and rich tool set. A one-time integration of the SimpleLink platform enables you to add any combination of the portfolio’s devices into your design, allowing 100 percent code reuse when your design requirements change. For more information, visit ti.com/simplelink.

In this reference design, the CC1352R is used to connect to initialize the IWR1642, connect to a wireless sensor network, and transmit all people counting and tracking data to the network.
2.3.3 IWR6843ISK and MMWAVEICBOOST: mmWave EVMs

IWR6843ISK and MMWAVEICBOOST are part of the mmWave EVMs hardware platforms. The IWR6843 Industrial starter kit (IWR6843ISK) from Texas Instruments is an easy-to-use evaluation module for the IWR6843 mmwave sensing device and this board contains 60GHz mmwave Radar transceiver in which antennas are etched and act as Radar front-end board. The MMWAVEICBOOST is an add-on board used with TIs mmWave sensor used in all Starter Kits to provide more interfaces and PC connectivity to the mmWave sensors. The MMWAVEICBOOST board provides an interface for the mmWave Studio tool to configure the Radar device and capture the raw analog-to-digital converter (ADC) data using a capture board such as DCA1000 evaluation module (EVM). IWR6843ISK and MMWAVEICBOOST contains everything required to start developing software for on-chip C67x DSP core and low-power ARM R4F controllers. It provides interface to the MSP43xx boards through 40-pin LaunchPad™/BoosterPack™ connectors.

The IWR6843ISK device includes the following features:

- 60-pin, high-density (HD) connector for raw analog-to-digital converter (ADC) data over LVDS and trace data capability
- Long range on-board antenna
- Current sensors for all rails
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2.3.4 LAUNCHXL-CC1352R1: SimpleLink™ Multi-Band CC1352R Wireless MCU LaunchPad™ Development Kit

The CC1352R LaunchPad (LAUNCHXL-CC1352R1) is a microcontroller development kit for rapid prototyping featuring the CC1352R microcontroller.

- **LaunchPad with Sub-1GHz radio for wireless applications with integrated PCB trace antenna**
- **Broad band antenna supports both 868 MHz ISM band for Europe and 915 MHz ISM band for US with a single board**
- **On-board emulator gets you started with instant code development in CCS Cloud**
- **Can be used with both LaunchPad kit and SmartRF™ Studio applications**
- **Access all I/O signals with the BoosterPack plug-in module connectors**
- **Compatible with LCD BoosterPack**

This reference design uses two CC1352R LaunchPads to implement a sensor-collector network.

The MMWAVEICBOOST device includes the following features:

- **On-board PMIC**
- **Hosts Starter Kit using two 60-pin high-density (HD) connector for the high-speed ADC data over CSI or LVDS and emulator signals**
- **FTDI-based JTAG emulation with serial port for programming flash on the Starter Kit**
- **XDS110-UART based QSPI flash programming**
- **60-pin HD connector to interface with the DCA1000 EVM**
- **Two 20-pin LaunchPad connectors that leverage the ecosystem of the TI standard Launchpad and have all of the digital controls from the Radar chip**
- **Two onboard controller area network (CAN) transceivers**
- **On-board PMIC**
- **60-pin MIPI HD connector for JTAG trace**
- **On-board FTDI chip to provide PC interface for serial peripheral interface (SPI), general-purpose input/output (GPIO) controls and universal asynchronous receiver/transmitter (UART) loggers**
- **On-board current sensors and temperature sensors**

This reference design uses the IWR6843ISK and MMWAVEICBOOST to support all IWR6843 functions.
3 Hardware, Software, Testing Requirements, and Test Results

3.1 Required Hardware and Software

The following sections describe the hardware and software required to get started with the people counting and tracking using the mmWave radar sensor with sub-1 GHz reference design.

3.1.1 Hardware Setup

The TIDA-010022 design requires the following hardware:

- One mmWave sensor carrier card platform (MMWAVEICBOOST)
- One IWR6843 intelligent mmWave sensor standard antenna plug-in module (IWR6843ISK)
- Two CC1352 LaunchPads (LAUNCHXL-CC1352R1)
- One 5 V, 2.5 A or greater DC power supply

**NOTE:** Before making any hardware modifications to the IWR6843 boards, flash them by following the steps in Section 3.1.2.

The CC1352 LaunchPad can attach to the MMWAVEICBOOST board after some hardware modifications. Table 2 lists the hardware modifications for the MMWAVEICBOOST board.

Table 2. MMWAVEICBOOST Hardware Modifications

<table>
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<tr>
<th>MODIFICATION</th>
<th>REASON</th>
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<tr>
<td>Remove R91</td>
<td>Disconnects RADAR_HOSTINTR1 pin from LaunchPad</td>
</tr>
<tr>
<td>Add R81</td>
<td>Connects RADAR_MSS_LOGGER pin to LaunchPad</td>
</tr>
<tr>
<td>Add R122 and add jumper to J13 pin 2-3</td>
<td>Connects 3.3 V rail on MMWAVEICBOOST board to 3.3 V rail on CC1352 LaunchPad</td>
</tr>
<tr>
<td>Configure mux as follows: S1.1 OFF: SPI1 (Default) S1.2 ON: 40PIN S1.3 OFF: 40PIN/J16 S1.4 ON: FTDI/4PIN/J16 (Default) S1.5 OFF: 40/60PIN/FTDI S1.6 OFF: 40/60PIN (Default) S1.7 OFF: 40/60PIN S1.8 ON: 40PIN S1.9 OFF: 60PIN S1.10 ON: FTDI S1.11 ON: FTDI S1.12 ON: XDS110 (Default)</td>
<td>Enable 40-pin interface</td>
</tr>
</tbody>
</table>

The components that need to be removed from the MMWAVEICBOOST board are marked by the red squares in Figure 13. The components that need to be added are marked in blue squares. No modifications are needed on the IWR6843ISK board.
Some modifications are needed on the CC1352 LaunchPad that will be used as the sensor node. Remove the following jumpers: "5V", "3V3", "RXD", and "TXD" and switch the XDS110 power jumper to "Extern" Power. Remove the SMA connector for the external antenna (J7 on the schematics) on the CC1352 LaunchPad for it to mate with the MMWAVEICBOOST board (see Figure 14).

No hardware modifications are needed on the CC1352 LaunchPad that will be used as the collector node.

Figure 14. SMA Connector in CC1352 to be Removed (Sensor Board)

After all hardware modifications are completed, the IWR6843ISK board, MMWAVEICBOOST board, and one of the CC1352 LaunchPads can be assembled together to form the sensor node.

The sensor node (IWR6843 boards + CC1352) can be powered by connecting the 5-V power supply to the MMWAVEICEBOOST board and the collector node can be powered by connecting the USB power supply.
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Figure 15. Sensor Node (IWR6843 Boards + CC1352) Power Supply

Figure 16. Collector Node (CC1352 Only) Power Supply
3.1.2 Software Setup

3.1.2.1 Loading the CC1352 Firmware

Follow these steps to load the firmware on the CC1352 LaunchPads:

2. Open UniFlash and connect the sensor node and collector node to the PC.

NOTE: See Section 3.1.1 for details on setting up the IWR6843 boards and CC1352 LaunchPad.

3. Once the CC1352 is plugged into the PC, UniFlash will detect each individual device.

NOTE: Both the 5-V power supply and a USB cable are needed to program the sensor node, but only the USB cable is needed to program the collector node.

4. Highlight the device to be programmed and click the Start button.
5. In the Program section, under Flash Image(s), click the Browse button.
   a. If loading firmware for the collector, navigate to the TIDA-010022 firmware folder and select the collector_cc1352r1lp.out file.
   b. If loading firmware for the sensor, navigate to the TIDA-010022 firmware folder and select the sensor_cc1352r1lp.out file.
6. After selecting the correct image file, click the Load Image button.
7. If the image was loaded successfully, the message “[SUCCESS] Program Load load completed successfully” is displayed.

Figure 17. Detected Devices
3.1.2.2 Loading the IWR6843 Firmware

This reference design was tested with and includes the binary image for the 68xx People Counting demo included in the mmWave Sensors Industrial Toolbox v. 3.2.0.

Follow these steps to load the IWR6843 firmware:

**NOTE:** Make sure the CC1352 LaunchPad is not attached to the MMWAVEICBOOST board.

1. Connect the IWR6843ISK and MMWAVEICBOOST boards together as shown in Figure 19.
2. Plug in micro-USB cable and 5-V power supply to mmWave boards as shown in Figure 19.
3. Connect the mini-USB cable to your PC and check the COM ports in Windows Device Manager. Figure 20 shows how the mmWave setup exports two virtual COM ports:
   a. XDS110 Class Application/User UART (COM\textsubscript{UART}): Used for passing configuration data and firmware to the mmWave boards.
   b. XDS110 Class Auxiliary Data Port (COM\textsubscript{AUX}): Used to send processed radar data output.

4. Put the MMWAVEICBOOST in flashing mode by connecting jumpers on SOP0 and SOP2 as shown in Figure 21. Then reset the MMWAVEICBOOST with SW2.
5. Download and open http://www.ti.com/tool/UNIFLASH.
6. In the **New Configuration** section, locate and select *IWR6843 ES1.0*.
7. Click **Start** to proceed.
8. Click the **Settings & Utilities** tab. Under setup, fill the COM Port text box with the Application/User UART COM port number (COM UART) noted earlier.
9. In the **Program** tab, browse and locate the `PC_lab_xwr68xx.bin` file from the TIDA-010022 firmware folder.

10. Reset the board with SW2 and click on **Load Image**.
    a. **Successful Flash Procedure**: The UniFlash console should indicate: [SUCCESS] Program Load completed successfully
11. Power off the board and remove only the SOP2 jumper.
12. Make sure SOP2 has been removed and that the IWR6843 boards are power cycled. This puts the boards back in functional mode.
3.1.2.3 Starting the Firmware

Follow these steps to start the firmware on the sensor and collector nodes. Refer to Section 3.1.1 for instructions on setting up the sensor node hardware.

1. Power on the collector node (CC1352 only) with the USB power supply first, and then wait for the red LED “Red: DIO6” to be on.
2. Power on the sensor node (IWR6843 boards + CC1352) with 5.0-V power supply.
3. Reset the sensor node by pressing the SW2 (NRST) button on the MMWAVEICBOOST board (see Figure 23).
4. Press “BTN-2 DIO14” (on collector node) to permit nodes to join the network, the “Red: DIO6” LED should be blinking on the collector node to indicate the network is opened.
5. Once the sensor has joined the network, its red LED will turn on.
6. Press “BTN-2 DIO14” (on collector node) to stop permitting new nodes from joining the network.
7. Once the sensor node has joined a network and has waited 20 seconds for the IWR6843 device to power up, the CC1352 device will configure and start the mmWave.
8. On both sensor and collector nodes, the “Green: DIO7” LED will toggle on each successful transmission between the nodes.

Figure 23. Location of LEDs and Button
3.1.2.4 Building the Firmware

The firmware for this TI design is based on the collector and sensor example code provided with the TI 15.4 stack. Patches are included with this TI design to apply the necessary changes to the example code. Follow these steps to apply the patches and build the example code.

1. Download Simplelink-cc13x2-sdk (version 2.10.00.48) from http://www.ti.com/tool/SIMPLELINK-CC13X2-SDK.
2. Project > Import CCS project.
3. Search in C:\ti\simplelink_cc13x2_sdk_2_10_00_48\examples\rtos\CC1352R1_LAUNCHXL\ti154stack directory.
4. Import two projects: collector_cc1352r1lp and sensor_cc1352r1lp.
5. Apply the patch for collector node:
   a. Right-click collector_cc1352r1lp and go to Team > Apply patch…
   b. Apply the collector patch (patch is found in Software Files)
   c. Right-click collector_cc1352r1lp and go to Properties
   d. In Include Options, add folder ${PROJECT_ROOT}/Application/collector_new
   e. In Predefined Symbols, add MMWAVE_SENSOR
6. Apply patch for sensor node:
   a. Right-click sensor_cc1352r1lp and go to Team > Apply patch…
   b. Apply the sensor patch (patch is found in Software Files)
   c. Right-click sensor_cc1352r1lp and go to Properties
   d. In Include Options, add folder ${PROJECT_ROOT}/Application/sensor_new
   e. In Predefined Symbols, add MMWAVE_SENSOR
7. Build the collector node code using Code Composer Studio:
   a. Select "collector_cc1352r1lp" and right click it, find Build Project and click on it to build the project
   b. "***** Build Finished *****" should display under the Code Composer Studio console when the project is built successfully.
8. Build the sensor node code using Code Composer Studio:
   a. Select "sensor_cc1352r1lp" and right click it, find "Build Project" and click on it to build the project
   b. "***** Build Finished *****" should display under the Code Composer Studio console when the project is built successfully.
Figure 24. Adding Include Options for Collector Node

Figure 25. Adding Predefined Symbols for Collector Node
Figure 26. Adding Include Options for Sensor Node

Figure 27. Adding Predefined Symbols for Sensor Node
3.1.2.5 Viewing Collector Data Output

When the collector node USB is connected to the PC, the device manager should recognize the following COM ports:

- XDS110 Class Application/User UART
- XDS110 Class Auxiliary Data Port

Figure 28. COM Ports
Launch TeraTerm, select "Serial" and select the XDS110 Class Application/User UART COM port from the drop-down menu and click the OK button. Verify that the COM port has the settings as Figure 29 shows.

![TeraTerm Setup](image)

**Figure 29. TeraTerm Setup**

A TeraTerm macro is included to parse the output of the collector node. To launch the macro, select Control menu, then select Macro option. Navigate to the TIDA-010022 firmware folder and select mmWave_collector_macro.ttl.

![Macro](image)

**Figure 30. Macro**

### 3.1.2.6 Modifying the mmWave Configuration

The mmWave configuration can be modified by following these steps:

1. After applying the patch from building the firmware in Section 3.1.2.4, go to sensor_cc1352r1lp -> Application -> sensor_new -> mmwave_sensor.c
2. Inside mmwave_sensor.c, find "const char *CommandList[]".
3. Add, remove, or modify commands as needed and rebuild the sensor project.

```c
const char *CommandList[] = {
  "dfeDataOutputMode 1\r",
  "channelCfg 15 5 0\r",
  "adcCfg 2 1\r",
};
```
"adcbufCfg 0 1 1 1\r",
"profileCfg 0 60.6 30 10 62 0 0 53 1 128 2500 0 0 30\r",
"chirpCfg 0 0 0 0 0 0 0 1\r",
"chirpCfg 1 1 0 0 0 0 4\r",
"frameCfg 0 1 128 0 50 1 0\r",
"lowPower 0 0\r",
"guiMonitor 1 1 1 0 0\r",
"cfarCfg 6 4 4 4 4 16 16 4 4 50 62 0\r",
"doaCfg 600 1875 30 1 1 0\r",
"SceneryParam -6 6 0.5 6\r",
"GatingParam 4 3 2 0\r",
"StateParam 10 5 100 100 5\r",
"AllocationParam 250 250 0.25 10 1 2\r",
"AccelerationParam 1 1 1\r",
"PointCloudEn 0\r",
"trackingCfg 1 2 250 20 52 82 50 90\r",
"sensorStart\r";

3.2 Testing and Results

3.2.1 Test Setup

3.2.1.1 People Counting Setup

For best results, the sensor node should be positioned high enough to be above the top of tracked objects and with a slight down tilt. The aim is to position the sensor node so that the antenna beam can encompass the area of interest. If the down tilt is too severe, noise from ground clutter increases and the effective sensing area decreases. If there is no down tilt, counting performance would be worse for cases in which one person is in line with and shielded by another person. Given the antenna radiation pattern of the sensor node, consideration should be taken to not mount the sensor node too close or oriented with the beam directed to the ceiling as this can increase the noise floor and result in less optimal performance.

Setup Requirements:

- Elevate Sensor Node 1.5–2.5 m high
- Down tilt: approximately 10 degrees

Setup using suggested tripod and smartphone clamp mount:

1. Screw on clamp mount to tripod
2. Clamp the sensor node across its width below the power barrel jack to attach sensor node.
3. Adjust the tripod head for approximately 10 degree downward tilt (Tip: Bubble or level smartphone applications can be used to measure down tilt)
4. Plug in the 5-V power supply to the sensor node
5. Extend the tripod so that the sensor node is elevated 1.5–2.5 m from the ground
6. Position the sensor node and tripod assembly in the desired location of room. The sensor node should be positioned so that the 120 degree FOV of the radar antenna encompasses the area of interest and points to the region in which people are expected to enter the space.
3.2.1.2 **Power Consumption**

The power consumption of the sensor (IWR6843 + CC1352) can be measured by connecting a bench power supply to the sensor.

![Power Consumption Measurement With Bench Power Supply Diagram](image)

3.2.1.3 **Wireless RF Range**

The range of the wireless sub-1 GHz RF was measured using two CC1352 LaunchPads. One CC1352 LaunchPad was set up as a collector, and the other set up as the sensor. For this test, the sensor LaunchPad remained at a stationary location as the collector LaunchPad was moved away. While the collector LaunchPad was on the move, the collector was continuously receiving the data from the sensor to make sure there were radio packets constantly being transmitted. The distance at which packets were no longer received was then measured.

3.2.2 **Test Results**

3.2.2.1 **People Counting Test Results**

For more detailed information on the people-counting test results, see *People Tracking and Counting Reference Design Using mmWave Radar Sensor*.
3.2.2.2 Power Characterization

The results of the power measurements are given in Table 3. The current was measured at the input of the MMWAVEICBOOST board. The current consumption includes all devices on the IWR6843 and CC1352 boards.

Table 3. Power Characterization

<table>
<thead>
<tr>
<th>SENSOR STATE</th>
<th>DESCRIPTION</th>
<th>MEASUREMENT</th>
</tr>
</thead>
<tbody>
<tr>
<td>Reset</td>
<td>All boards in reset</td>
<td>5 V x 287 mA = 1.44 W</td>
</tr>
<tr>
<td>Idle</td>
<td>mmWave radar inactive, no wireless packets</td>
<td>5 V x 500 mA = 2.50 W</td>
</tr>
<tr>
<td>Active</td>
<td>mmWave radar actively tracking and wireless communication</td>
<td>5 V x 670 mA = 3.35 W</td>
</tr>
</tbody>
</table>

3.2.2.3 Wireless RF Range Results

The wireless RF range was measured to be approximately 70 m in a typical office environment with a direct line of sight.

There are ways to increase this distance even further. Using a whip antenna with gain instead of the passive PCB antenna could offer improvements in the wireless RF range. Another option would be to increase the transmit power of the CC1352 device at the expense of increased supply current during the radio transmission intervals.
4 Design Files

4.1 Schematics
To download the schematics for the board, see the design files at TIDA-010022.

4.2 Bill of Materials
To download the bill of materials for the board, see the design files at TIDA-010022.

4.3 PCB Layout Recommendations
To download the PCB layout recommendations for the board, see the design files at TIDA-010022.

4.4 Altium Project
To download the Altium Designer® project for the board, see the design files at TIDA-010022.

4.5 Gerber Files
To download the Gerber Files for the board, see the design files at TIDA-010022.

4.6 Assembly Drawings
To download the assembly drawings for the board, see the design files at TIDA-010022.

5 Software Files
To download the software files, see the design files at TIDA-010022.

6 Related Documentation
1. Texas Instruments, *IWR6843 single-chip 60- to 64-GHz mmWave sensor data sheet*
2. Texas Instruments, *CC1352R SimpleLink™ high-performance dual-band wireless MCU data sheet*
3. Texas Instruments, *LP87702-Q1 dual buck converter and 5-V boost with diagnostic functions data sheet*
4. Texas Instruments, *LM53625/35-Q1, 2.5-A or 3.5-A, 36-V synchronous, 2.1-MHz, step-down DC-DC converter data sheet*
5. Texas Instruments, *People tracking and counting reference design using mmWave radar sensor design guide*

7 Trademarks
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8 About the Author

LING LIN is an intern in the Building Automation System Engineering & Marketing (SEM) at Texas Instruments, where he is responsible for developing reference design solution for the connectivity between mmWave Radar Sensor and dual-band wireless communication. Ling just finished studying bachelor’s degree at University of Florida, will continue graduate school at University of Texas, Austin.

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# Revision History

NOTE: Page numbers for previous revisions may differ from page numbers in the current version.

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<tr>
<th>Changes from Original (August 2018) to A Revision</th>
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<td>Changed IWR1642 to IWR6843 throughout document</td>
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<td>Deleted IWR1642, LP87524B-Q1, TPS7A8101, and TPS7A88-Q1 from Resources</td>
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<tr>
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<td>Changed MMAVEICBOOST Front PCB Layout View image</td>
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