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Analytical and experimental comparisons between the frequency-modulated–frequency-shift measurement and the pulsed-wave–time-shift measurement Doppler systems

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In previous publications, a new echo-ranging Doppler system based on transmission of repetitive coherent frequency-modulated (FM) sinusoids in two different implementations was presented. One of these implementations, the frequency-modulated–frequency-shift measurement (FM–fsm) Doppler system is, in this paper, compared with its pulsed-wave counterpart, the pulsed-wave–time-shift measurement (PW–tsm) Doppler system. When using transmitted PW and FM signals with a Gaussian envelope, the parallelism between the two systems can be stated explicitly and comparison can be made between the main performance indices for the two Doppler systems. The performance of the FM and PW Doppler systems is evaluated by means of numerical simulation and measurements of actual flow profiles. The results indicate that the two Doppler systems have very similar levels of performance. © 1996 Acoustical Society of America.

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LIST OF SYMBOLS

- $B_0 = f_2 - f_1$, frequency excursion of transmitted signal
- $B_{rms}$ rms bandwidth of transmitted signal
- $D$ nominal range
- $\Delta D$ axial range cell distance defined by signal processing
- $d^{(n)} = d^{(0)} + v_n T_s$, range of scatterer at the onset of $n$th transmission
- $f_0$ center frequency of transmitted signal; for FM: $f_0 = (f_1 + f_2)/2$
- $f_1$ ‘‘start’’ instantaneous frequency of transmitted sweep signal ($t = 0$)
- $f_2$ ‘‘stop’’ instantaneous frequency of transmitted sweep signal ($t = t_m$)
- $\Delta f_n$ $= \tau_0 S_0$, change in position frequency between two consecutive fsm spectra
- $f_a^{(n)} = (f^{(n)} - t_s) S_0$, position (or center) frequency of the fsm spectrum
- $f_w = (2\Delta D/c) S_0$, width of spectral window in fsm signal processing
- $S_0 = B_0 t_m$, sweep rate of transmitted FM signal
- $t^{(n)} = 2d^{(n)}/c$, ultrasound round trip travel time for scatterer at the onset of transmission number $n$
- $t_a^{(n)}$ measure of rate of oscillations of the $n$th spectral cross-correlation function in the FM–fsm Doppler system
- $t_d = t^{(n)} - t$, difference between acoustic delay ($t^{(n)}$) and system delay ($t_s$)
- $t_m$ time duration of transmitted signal
- $T_p$ pulse or sweep repetition time
- $T_s = 2\Delta D/c$, time delay corresponding to nominal range
- $T_w = 2\Delta D/c$, duration of time window in tsm signal processing
- $v$ velocity component of target (scatterer) along ultrasound beam
- $v_{alias}$ aliasing velocity in a psm Doppler system
- $\alpha$ form factor for Gaussian envelope
- $\alpha_G = 2(\Delta t_m)^2$, combined form factor
- $\beta = (c - v)/(c + v)$, Doppler compression factor
- $\gamma = 2vT_s/c$, change in round-trip travel time between consecutive received signals

INTRODUCTION

The noninvasive assessment of blood flow with Doppler ultrasound is, today, a standard technique in hospitals and clinics. It is used extensively for studying cardiac hemodynamics and the flow patterns in arteries and veins (e.g., carotid artery). The prevailing technique is PW (pulsed-wave) Doppler in which a series of short bursts of ultrasound energy is transmitted. From the Doppler compression of the backscattered signal from the moving red blood cells, the velocity of the blood can be estimated. This may be done with either the conventional$^{1,2}$ technique, based on phase-shift measurement (PW–psm)$^3$ or with a newer technique, utilizing time-shift measurement (PW–tsm)$^{4,5}$.

However, the use of sound bursts of short time duration results in a high peak transmitted power. To reduce this, but...
at the same time maintain the wide bandwidth of the transmitted signal, several types of coded transmission signals have been devised, such as random noise \(^9,10\) and pseudorandom noise.\(^1,12\) A common element in these approaches is the use of phase-shift measurements in the signal processing. In contrast, the Doppler system presented here utilizes coherent, repetitive frequency-modulated (FM) signals as transmission signals where the velocity information may be extracted either with phase shift measurement (FM–psm) or frequency-shift measurement (FM–fsm).\(^1,13,14\) The signal theory and systems description for these two versions of the FM Doppler system were presented in two previous papers.\(^14,15\) It was shown that the FM–psm and FM–fsm Doppler techniques in several respects are analogous to the PW–psm and PW–tsm techniques, respectively. Simultaneous transmission and reception is generally utilized in the FM Doppler system, thus requiring a dual transducer system.

In this paper, the FM–fsm technique will be contrasted analytically and experimentally with the PW–tsm technique, as FM–fsm appears to offer unique advantages over FM–psm, such as reduced influence of medium attenuation. In addition, the PW–tsm and FM–fsm techniques have the potential of avoiding the velocity aliasing phenomena, known from psm signal processing. By weighting the transmitted signals with a Gaussian envelope, closed form expressions are obtainable for the relevant signals, spectra, and cross-correlation functions for both FM–fsm and PW–psm. Furthermore, the Gaussian envelope gives a fairly realistic representation of the electro-acoustic transfer function of actual broadband transducers. Exploiting the parallelism between the FM–fsm and the PW–tsm Doppler systems, it is shown that the two main performance indices (range cell size and accuracy in the velocity estimation) are comparable.

The paper contains the following parts: In Sec. I, the mathematical expressions for the transmitted signal for both FM and PW Doppler systems are stated together with expressions for the rms bandwidth. In Sec. II, the received signal for a single scatterer is given, and the FM–fsm Doppler system is analyzed and contrasted with the PW–tsm Doppler system in Sec. III. Section IV describes the parallels between the two systems and argues that the performance indices are roughly identical. Finally, simulation results and experimental results are presented in Secs. V and VI, respectively.

I. THE TRANSMITTED SIGNAL

The transmitted signal for the FM Doppler system consists of a series of linearly frequency-modulated sinusoids (sweeps) with a Gaussian envelope function that is truncated to be zero outside the interval \([0; t_m]\). Specifically, a sweep of duration \(t_m\) seconds is transmitted every \(T_r\) seconds \((T_r > t_m)\); \(T_r\) is thus the sweep repetition time. The entire transmitted signal consists of a total of \(L\) individual sweep signals, labeled 0 to \(L-1\). A given transmitted signal and corresponding received signal are denoted by the superscript \((n)\), but as all the individual transmitted sweeps are identical, the \(n\) notation is only used for the received signals. In the following derivations, local time—denoted \(t\)—is used, which means that \(t=0\) at the onset of each transmitted sweep. The transmitted signal for the PW Doppler system consists of a corresponding series of short duration bursts, also with a Gaussian envelope, with a burst interval of \(T_r\) seconds.

For the purpose of deriving analytic solutions to the signals and parameters, generated by the signal processing of the received signals, Gaussian enveloped signals extending over the interval \(]-\infty;\infty[\) will be used, so that one transmitted signal can be expressed in the following form:

\[
g_t(t) = \text{Re}\{\tilde{g}_t(t)\} = \text{Re}\left\{\exp\left[-2\left(\frac{\alpha}{t_m}\right)^2 \left(t - \frac{t_m^2}{2}\right)\right]\right\}
\times \exp[j(2\pi f_1 t + \pi S_0 t^2)], \tag{1}
\]

where tilde \((\sim)\) denotes complex variables and \(\text{Re} \{ \} \) extracts the real part. An example of this signal is shown in Fig. 1. In (1), \(t_m\) is the time duration of the truncated sweep signal used in the actual implementation. If \(\alpha=3\), then the value of the envelope function at \(t=0\) and \(t=t_m\) will be \(\approx 1\%\) of the maximum value obtained at \(t=t_m/2\). This \(\alpha\) value is also used by Harris.\(^16\) With an appropriate choice of \(\alpha\), such as the one used above, the difference between \(g_t(t)\), as given in (1), and the truncated \(g_t(t)\), used in the actual measurement system, is negligible. The analytical results will be derived from the untruncated \(g_t(t)\) where it is assumed that each set of transmitted and received signals is unaffected by the \(L-1\) other sets. For the complex version of the sweep signal, \(\tilde{g}_t(t)\), it is seen that the instantaneous frequency at \(t=0\) is \(f_1\) and the instantaneous frequency at \(t=t_m\)
is $f_2=f_1+S_d p_m$. These two frequencies are hereafter called start and stop frequencies, respectively, as they indicate the sweep range in a physical system. The frequency excursion, produced during $t_m$, is thus $B_0=f_2-f_1$. The center frequency of the spectrum of the signal in (1) is $f_0=(f_1+f_2)/2$ which, in general, is assumed to be equal to the center frequency of the transducer. It is finally noted that a PW excitation signal can be obtained from (1) by setting $S_0=0$, replacing $f_1$ with $f_2$ and using a much smaller $t_m$ value, chosen to match the PW bandwidth with that of the sweep signal.

The magnitude spectrum of a signal with a Gaussian envelope is Gaussian as well. The rms bandwidth in Hz of $g_t(t)$, as given in (1), can be found to be

$$B_{FM,\text{rms}} = \sqrt{\frac{\int_{-\infty}^{\infty} f^2 |\tilde{G}_s(f)|^2 df}{\int_{-\infty}^{\infty} |\tilde{G}_s(f)|^2 df}} \frac{B_0^2}{8 \alpha^2 + \frac{\alpha^2}{2 \pi^2 t_{m,FM}^2}} ,$$

where $\tilde{G}_s(f)$ is the spectrum of $g_t(t)$. It is seen that the bandwidth expression combines contributions from both the signal parameters, $t_m$ and $\alpha$, and from the frequency excursion, $B_0$.

From (2), it is seen that the rms bandwidth of a transmitted PW signal ($B_0=0$) is

$$B_{PW,\text{rms}} = \frac{1}{\sqrt{2\pi}} \frac{\alpha}{t_{m,PW}} = \frac{1}{4 \pi \frac{t_{m,FM}}{t_{m,PW,\text{rms}}}},$$

where $t_{m,PW}$ is the duration of the transmitted PW burst and $t_{m,FM,\text{rms}} = t_{m,PW}/(2\sqrt{2} \alpha)$ is the corresponding rms duration. To make a valid comparison between the two Doppler techniques, the operating conditions must be identical, which, among other things, requires the same bandwidth of the transmitted signals. Thus applying $B_{FM,\text{rms}}=B_{PW,\text{rms}}$ to (2) and (3) yields

$$\frac{1}{t_{m,PW}} = \frac{\pi^2}{4 \alpha} B_0^2 + \frac{1}{t_{m,FM}},$$

where $\alpha$ is assumed identical for the two systems and $t_{m,PW}$ and $t_{m,FM}$ are the lengths of the transmitted PW and FM signals, respectively. For the case when

$$\frac{\pi^2}{4 \alpha} B_0^2 \gg \frac{1}{t_{m,FM}},$$

i.e., the contribution from $B_0$ dominates, (4) simplifies to

$$t_{m,PW} = \frac{2 \alpha^2}{\pi B_0}.$$  

(5)

Thus $t_m$ for the PW Doppler system will be determined from $\alpha$ and the chosen frequency excursion, $B_0$, for the corresponding FM Doppler system. It is assumed throughout the paper that (5) is fulfilled and (6), therefore, is valid.

II. THE RECEIVED SIGNAL

The received signal, based on the excitation in (1), will now be found for the idealized measurement situation illustrated in Fig. 1. A single scatterer, with a frequency-independent backscattering coefficient $r$, is moving axially away from the transducer with velocity $v$. The term backscattering coefficient is here chosen to mean the ratio of the transmitted pressure amplitude (plane wave) to the received pressure amplitude, at the location of the receiving transducer. As shown in Fig. 1, the range of the particle is $d_0$ at $t=0$ and $n=0$. The propagation speed of sound in the medium between the particle and transducer is $c$, and the medium is assumed to be perfectly elastic. The scatterer is assumed insonified with a plane-wave pressure field from the transducer, the time dependence of which is described by (1).

For the signal analysis performed here, the bandlimited signal, $g_t(t)$, is applied to the transducer which is assumed to have a flat frequency response. In contrast, a constant amplitude sweep signal is applied in the physical implementation where the shaping of the envelope of the received signal—in the paper assumed to be Gaussian—is introduced by the bandlimited frequency response of the transducer. Under the given assumptions, the $n$th received signal is a time-shifted and Doppler-compressed replica of the $n$th transmitted signal

$$g_t^{(n)}(t) = r g_t \left[ \beta \left( t - \frac{d_0^{(n)}}{c-v} \right) \right],$$

where $\beta = (c-v)/(c+v)$ ($\beta$ is the reciprocal of the $\beta$ defined in Ref. 15) is the Doppler compression factor, and $d_0^{(n)} = d_0^{(0)} + nt$, describes the range of the scatterer at the onset of the $n$th transmission. Applying (1) to (7) yields the received signal, $g_t^{(n)}(t)$, where it is assumed that $g_t(t)$ in (1) only exists in the time interval $0 \leq t \leq t_m$:

$$g_t^{(n)}(t) = \text{Re} \left[ r \exp \left[ -\alpha_G \left( \beta t - 2 \frac{B_0^{(n)}}{c-v} \frac{t_m}{2} \right)^2 \right] \right.$$

$$\left. \times \exp \left[ j 2 \pi f_1 \beta \left( t - \frac{d_0^{(n)}}{c-v} \right) + \pi S_0 \beta^2 \right] \right. $$

$$\left. \times \left( t - \frac{2 d_0^{(n)}}{c-v} \right) \right],$$

$$\frac{2 d_0^{(n)}}{c-v} \leq t \leq \frac{2 d_0^{(n)}}{c-v} + \frac{t_m}{\beta}. $$

(8)

where the bounds for the time duration is given in the last line of (8). Outside this time interval, $g_t^{(n)}(t)$ is zero. Note that $\alpha_G = 2(\alpha t_m)^2$ has been introduced to simplify the notation. When comparing (1) with (8), two distinct effects are seen. First, the received signal is expanded (or compressed when $v$ is negative) so that its duration is $t_m/\beta$. Due to this expansion (or compression), the start frequency and the sweep rate have been Doppler shifted as well. These effects have been analyzed elsewhere. The second effect that can be noted from (8) is that the arrival time of the received signals occurs with an increasing delay, relative to transmission, as the particle moves away. This corresponds to the Doppler shift of the sweep (burst) repetition time, so that the new sweep (burst) repetition time is $T_1^{(n)} = T_1 / \beta$. For the single scatterer, it is this effect that is measured with the PW and FM Doppler systems, considered here. In the case of
multiple scatterers moving with a uniform velocity, this effect is observed as a shift in the signature of consecutive received signals. Ignoring the Doppler expansion (or compression) of the individual signals, i.e., setting $\beta = 1$ and linearizing so that $c - \nu = c$, (8) can be written as

$$g_R^{(n)}(t) = \text{Re}\{r \exp[-\alpha_c(t - t^{(n)}) - t_m/2] \times \exp[j(2\pi f_1(t - t^{(n)}) + \pi S_0(t - t^{(n)})^2)]\},$$

where

$$t^{(n)} = t_0 + d_i^{(0)} = 2d^{(0)} + n \nu T_c = 2d^{(0)} / c + n \tau_0.$$ \hspace{1cm} (10)

In (10), $\tau_0 = T_r - T'_r = (2\nu/c) T_r$ represents the change in round-trip travel time between consecutive sweeps.

Finally, consider the situation in which a large, but finite number, $q$, of scatterers moving with the same velocity are present in the ultrasound beam. In this case we assume that the total received signal can be written as a summation of individual received signals given in (9), i.e., no multiple scattering is considered. The total received signal is

$$g_R^{(n)}(t) = \sum_{i=1}^{q} g_{r,i}^{(n)}(t),$$ \hspace{1cm} (11)

where a backscattering coefficient $r_i$ and an initial range $d_i^{(0)}$ is associated with the $i$th scatterer. The subscript $R$ is employed to distinguish $g_R^{(n)}(t)$ from the received signal due to one scatterer, $g_{r,i}^{(n)}(t)$. Note that the model assumes some idealizations of the physical reality which increase the correlation between consecutive received signals and thus improves the performance. The most significant of the excluded effects are lateral variation in ultrasound beam intensity and velocity variation within the range cell. Nor does the model take into account the frequency-dependent attenuation in the medium.

It is thus assumed that the received signal from blood can be modeled as a summation of the contributions from a large number of such scatterers located randomly within a plane. Even though the analysis of the Doppler systems to follow will be based on one scatterer, the multiscatterer situation can quite easily be obtained by the use of the principle of superposition.

III. FM–fsm SIGNAL PROCESSING

In this section the FM–fsm signal processing is developed and contrasted with the PW–tsm method. First, a short description of the PW–tsm method is given.

The block diagram for the PW–tsm system is displayed in Fig. 2 with the switch in PW position. A burst generator and power amplifier generate the transmitted signal which is applied to the single crystal transducer via the transmit/receive switch. Consider the transmitted signal to be a short burst as described by (1) with $S_0 = 0$, $f_1 = f_2 = f_0$, and $t_m$ equal to a few cycles at $f_0$, as specified in (6). The received signal can be bandpass filtered, to remove noise lying outside the spectral range of the signal. Following that, a segment of the received signal is extracted with the range gate window (length $T_w$), delayed by $T_r$ seconds and cross-correlated with the subsequent received signal. A search window is next applied to the cross-correlation function, and from the location of the peak inside this search window, the target velocity can be calculated. The width of the search window corresponds to one cycle of $f_0$ with the effect that, with a high probability, only one peak can be found inside the search window. This minimizes the possibilities for detecting a sidelobe in the cross-correlation function, but the velocity range will be restricted to $\pm v_{\text{alias}}$, where $v_{\text{alias}} = c/(4f_0 T_r)$ is the aliasing velocity for a psm Doppler system. The actual axial resolution distance for this system is determined by contributions from both $\Delta D_{\text{pw}} = c T_r/2$ and the minimum obtainable axial range resolution distance, $\Delta D_{\text{min}} = c/(2B)$, where $B$ is the bandwidth of the transmitted signal.

The FM–fsm signal processing utilizes cross-correlation of real spectra for extracting velocity information, in a fashion quite similar to the cross-correlation of real time signals in the PW–tsm Doppler system. In previous publications, a simpler version of the FM–fsm Doppler system was presented, based on the cross correlation of magnitude spectra. Greater precision is obtainable with cross correlation of real spectra, due to the more narrow peak in the cross-correlation function. The received signal in the FM–fsm Doppler system is basically a linear sweep signal which must be preprocessed in order to establish a unique range-frequency relationship analogous to the range–time relationship known from PW excitation. The FM–fsm preprocessing is similar to what is done in time delay spectrometry (TDS).
specifically, in the preprocessing, a given received sweep signal is demodulated by using a reference sweep, and the demodulated signal is subsequently transformed into the frequency domain. The resulting spectrum is called the fsm spectrum. This fsm spectrum, as will be shown later, is analogous to the received signal due to PW excitation and is shown in Fig. 3(a) where the transmitted signal, except that the amplitude is constant, not reference signal which is a delayed analytic version of the transmitted signal, the preprocessing is completed. Further processing is done along the same lines as for the PW–tsm Doppler system: A segment around $f=0$ of width $f_w$ is isolated from the fsm spectrum, $G_a^{(n)}(f)$, and then cross correlated with the subsequent fsm spectrum, $G_a^{(n+1)}(f)$. Different components of $G_a^{(n)}(f)$ and $G_a^{(n+1)}(f)$ may be chosen.

**A. FM-fsm preprocessing**

The first step of the preprocessing consists of quadrature demodulation of the received sweep signals as shown in the block diagram in Fig. 2. A numeric example of the transmitted sweep signal is illustrated in Fig. 3(a), while two consecutive received signals from one moving particle are shown in Fig. 3(b) and (c). The quadrature demodulation is done by multiplying each received signal with the following reference signal which is a delayed analytic version of the transmitted signal, except that the amplitude is constant, not Gaussian:

$$g_{\text{ref}}(t) = \exp\left\{j(2\pi f_0(t-t_s) + \pi S_0(t-t_s)^2)\right\},$$

where $t_s = 2Dc/\nu$ and $D$ is the nominal range or range of interest. The multiplier output is filtered with an ideal low-pass filter (LP) with gain $2$, for the purpose of eliminating the sum frequencies generated by the multiplication. The output of the filter is called $\overline{g}_a^{(n)}(t)$. Thus

$$\overline{g}_a^{(n)}(t) = 2LP\{g_r^{(n)}(t)g_{\text{ref}}(t)\}.$$

For a single particle, the demodulated signal is a tone burst with Gaussian envelope and duration $t_m$. The mean frequency of this tone burst is proportional to the axial displacement of the particle from $D$. Two consecutive demodulated signals are shown in Fig. 3(d) and (e). Next, in the second step of the preprocessing, the demodulated signal is Fourier transformed into the frequency domain, with a temporal zero reference of $t=t_s$. The resulting spectrum, $G_a^{(n)}(f)$, is called the fsm spectrum. Figure 3(f) and (g) show the real and magnitude parts of two consecutive fsm spectra. As will be shown, consecutive fsm magnitude spectra are identical in shape, but shifted in frequency. The phase function changes from one fsm spectrum to the next, causing the real part of consecutive fsm spectra to differ both in frequency and in shape of the spectral waveform. The derivation of $G_a^{(n)}(f)$ is given in Appendix A with the following result:

$$G_a^{(n)}(f) = \sqrt{\frac{\pi}{\alpha_G}} \exp\left[-\frac{\pi^2}{\alpha_G} (f_a^{(n)} - f)^2\right] \times \exp\left[j2\pi \left(\frac{f_a^{(n)} + f}{2}\right) + j\varphi_b^{(n)}\right],$$

where

$$f_a^{(n)} = (t^{(n)} - t_s),$$

$$f_a^{(n)} = \frac{2(D^{(n)} - D)}{S_0},$$

and

$$\varphi_b^{(n)} = \pi t_s^{(n)} (2f_1 - S_0 d^{(n)}).$$

The frequency value, $f_a^{(n)}$, defined in (15), is called the position frequency of the fsm spectrum. This frequency is proportional to the difference between the actual range of the particle, $d^{(n)}$, and the nominal range, $D$.

When the FM Doppler system is implemented to provide a velocity profile, the velocity for a set of nominal ranges, $D_i$, must be found. In the implementation presented in this paper, each range must be treated individually, requiring a new $D$ and FT per velocity estimate or range cell. More efficient approaches can be envisioned, but these are beyond the scope of this paper.

**B. Determination of the spectral cross-correlation function**

When $G_a^{(n)}(f)$ in (14) has been obtained from the received signal, the preprocessing is completed. Further processing is done along the same lines as for the PW–tsm Doppler system: A segment around $f=0$ of width $f_w$ is isolated from the fsm spectrum, $G_a^{(n)}(f)$, and then cross correlated with the subsequent fsm spectrum, $G_a^{(n+1)}(f)$. Different components of $G_a^{(n)}(f)$ and $G_a^{(n+1)}(f)$ may be chosen.

![FIG. 3. Signals and spectra of the FM–fsm system. (a) Transmitted signal, $g_r(t)$. (b) and (c) First and second received signals, $g_{r1}^{(n)}(t)$ and $g_{r2}^{(n)}(t)$, respectively. (d) and (e) First and second demodulated signals, $g_a^{(n)}(t)$ and $g_a^{(s)}(t)$, respectively. Note that $g_a^{(n)}(t)$ is further delayed than $g_a^{(s)}(t)$ and that the mean frequency of $g_a^{(n)}(t)$ is higher than that of $g_a^{(s)}(t)$. (f) and (g) Real part (——) and magnitude (…) of first and second fsm spectra, $G_a^{(n)}(f)$ and $G_a^{(s)}(f)$, respectively. Note that these spectra oscillate at different rates and occupy different frequency ranges. The parameters are: $f_0 = 5$ MHz, $B_s = 5$ MHz, $t_w = 400f_0$, $\alpha_G = 2(3t_m)^2$. $f_s = 20f_0$. The ordinate is a relative scale from $-1$ to $1$.](https://asadl.org/journals/doc/ASALIB-home/info/terms.jsp)
for the cross-correlation. In our previous papers (Refs. 14
and 15), only the cross-correlation of the spectral magnitude
was considered, whereas—as will be described—the empha-
sis in this paper is on cross correlation of the real com-
ponents of the spectra. From the location of the peak in the
cross-correlation function, the velocity in the range cell is
estimated.

The axial range resolution distance is considered first.
The relation between spectral window width, \( f_w \), and cor-
responding axial extent of the range cell in the medium is
\[ \Delta D_{FM} = \frac{c f_w}{2 S_0}, \] (17)
which is analogous to the axial range resolution distance,
\( \Delta D_{pw} = (c/2) T_w \), for the PW–tsm Doppler system.

Before continuing with the cross-correlation function, some
observations concerning (14) must be made. It is seen from
(15) and (10) that consecutive magnitude fsm spectra are
displaced by an amount
\[ \Delta f_a = f_a^{(n+1)} - f_a^{(n)} = \frac{2 \nu T_r}{c} S_0 = \tau_0 S_0. \] (18)
The spectral shift, \( \Delta f_a \), is equal to the time shift between
consecutive received PW signals multiplied with the time
to frequency conversion factor, \( S_0 \). Specifically, it is seen that
\[ | \tilde{G}_a^{(n+1)}(f) | = | \tilde{G}_a^{(n)}(f - \Delta f_a) |, \] (19)
while
\[ \tilde{G}_a^{(n+1)}(f) \neq \tilde{G}_a^{(n)}(f - \Delta f_a). \] (20)
The latter inequality is due to the fact that the time signals
from which \( \tilde{G}_a^{(n)}(f) \) and \( \tilde{G}_a^{(n+1)}(f) \) are generated are
shifted both in frequency and in time causing the phase of
\( \tilde{G}_a^{(n)}(f) \) to be shifted relatively to the phase of \( \tilde{G}_a^{(n+1)}(f) \).
This can be observed by comparing plot (d) with plot (e)
in Fig. 3. Also, note that the rate of oscillation of the real parts
is changed by only a small amount (the relative increase is
\((4 \nu/c) T_r / f_m \)). This means that the unique waveform signa-
ture present in received PW signals at a given range is not
preserved in the real or imaginary part of received PW signals
but is preserved in the real or imaginary part of \( \tilde{G}_a^{(n)}(f) \).
However, as will be shown, this does not remove the possibility
for velocity detection from the real part of the cross-correlation
function. Whereas the result of the cross-correlation of mag-
nitude spectra\(^ {14} \) can be interpreted directly by using (18),
the result of cross-correlating real spectra is influenced by
additional factors; nonetheless, peak detection based on the more
rapidly oscillating real spectra is likely to be more precise.

The cross-correlation function for one scatterer will now be
considered. In this case, the range-gate window can be
ignored which makes it possible to write the complex cross-
correlation function of two consecutive fsm spectra in (14) as
follows:
\[ \tilde{C}_{FM}^{(n,n+1)}(\gamma) = \int_{-\infty}^{\infty} \tilde{G}_a^{(n)}(f) \tilde{G}_a^{(n+1)\#}(f + \gamma) df, \] (21)
where * denotes complex conjugation. Inserting (14) and
\( n \) and \( n+1 \) into (21) allows an analytical solution to (21) to be
derived. In Appendix B, this complex-valued cross-
correlation function has been found to be
\[ \tilde{C}_{FM}^{(n,n+1)}(\gamma) = \frac{c 2 \alpha_{G}^{2}}{2} \exp \left[ - \frac{\pi^2}{2 \alpha_{G}^{2}} (\Delta f_a - \gamma)^2 \right] \times \exp \left[ - j \pi \frac{\Delta f_a}{2} (\Delta f_a - \gamma) + j \varphi_{c}^{(n)} \right]. \] (22)
where \( \alpha_{G} = r^{2} \sqrt{\pi/2 \alpha_{G}} \) and
\[ \varphi_{c}^{(n)} = \pi \tau_0 |S_0(2f_a^{(n)} + \tau_0) - 2 f_1|. \] (23)
The factor \( t_a^{(n)} \) in (22) determines the “rate of oscillation” of
the cross-correlation function where \( t_a^{(n)} / 2 \) is in cycles per
hertz:
\[ t_a^{(n)} = t_a^{(n+1)} - 2 t_s + 2 t_a^{(n)} - 2 t_a^{(n+1)} \] (24)
The result in (22) is a complex sinusoid with a Gaussian
envelope. The real part of (22) is
\[ C_{FM}^{(n,n+1)}(\gamma) = \Re \{ \tilde{C}_{FM}^{(n,n+1)}(\gamma) \} = \frac{\alpha_{G} \nu}{2} \exp \left[ - \frac{\pi^2}{2 \alpha_{G}^{2}} (\Delta f_a - \gamma)^2 \right] \times \cos \left[ - \pi t_a^{(n)} (\Delta f_a - \gamma) + \varphi_{c}^{(n)} \right]. \] (25)
which is identical to the cross-correlation of the real part of
consecutive fsm spectra. A good approximation to the global
maximum of the cross-correlation function in (25) has been
derived in Appendix C for the case when the velocity is
below the aliasing velocity, \( v_{\text{alias}} = c/(4f_0 T_r) \); this maximum
is given as
\[ \gamma_0 = \frac{2 T_r}{c} \left( S_0 + \frac{2 f_1}{t_m} \right) \nu \] (26)
An estimate of \( \gamma_0 \), based on actual data, is found as
\[ \hat{\gamma} = \arg \max_{\gamma} \{ \tilde{C}_{FM}^{(n,n+1)}(\gamma) \}. \] (27)
Using (26) and (27), the estimate of the particle velocity is
\[ \nu = \frac{\hat{\gamma}}{4 T_r c (f_0 / t_m)} = \frac{c \sqrt{8} a_{TM,\text{rms}}}{4 T_r f_0}, \] (28)
where the relation between \( t_m \) and rms duration of \( t_m \), i.e.,
\( t_m = \sqrt{8} a_{TM,\text{rms}} \),\(^ {18} \) has been used. A numeric example of two
consecutive fsm spectra is provided in Fig. 4, together with
the cross-correlation function between them. Both the mag-
nitude cross-correlation function and the complex-valued
cross-correlation function are shown. The locations of their
respective peaks are indicated.

The spectra in Fig. 4 were generated with the following
system parameters: \( f_0 = 3.5 \) MHz, \( B_0 = 5 \) MHz, \( T_r = 133.3 \) \mu s, \( t_m = 0.87 T_r = 106.7 \) \mu s, \( S_0 = 46.87 \) GHz/s, \( v_{\text{alias}} = c/(4f_0 T_r) = 0.8 \) m/s. The velocity of the scattered
wave
\[ \nu = 0.7 v_{\text{alias}} = 0.56 \) m/s. The peak of the magnitude function is
at \( 2 \nu T_r/c S_0 = 4.68 \) kHz, while the peak of the real function is
at \( 2 \nu T_r/c (S_0 + 2 f_1/t_m) = 6.56 \) kHz.
IV. COMPARISON BETWEEN PW–tsm AND FM–fsm DOPPLER SYSTEMS

Based on the description of the two Doppler systems in Sec. III, their relative performance will now be compared. As mentioned earlier, the performance of a Doppler system is evaluated by the size of the spatial resolution cell, and by how precisely the velocity is found within this resolution cell.

It is assumed that the rms bandwidths, $B_{PW,\text{rms}}$ and $B_{FM,\text{rms}}$, of the transmitted PW and FM signals, respectively, are identical. Also, the mean transmitted energy and the noise signal power level at the receiving transducers are assumed identical in the two Doppler systems. The validity of these assumptions in practice is discussed at the end of this section.

The range cell size (spatial resolution) is determined laterally by the beam dimensions and axially by the bandwidth of the transmitted/received signal and the window length (defined by $T_w$ or $f_w$, for PW–tsm and FM–fsm, respectively). In this paper, only the axial resolution distances are compared, as the lateral dimension is determined mainly by the transducer geometry and aperture size, i.e., transducer dimensions measured in wavelengths.

When the received signal in the PW Doppler system, $g^{(n)}(t)$, for one scatterer is compared with the fsm spectrum, $G^{(n)}(f)$, for one scatterer, several similarities and parallels are seen: First of all, when the scatterer is moved along the acoustic axis of the transducer, the envelope of the received PW signal, $|g^{(n)}(t)|$, is shifted on the time axis just as the fsm spectrum envelope, $|G^{(n)}(f)|$, is shifted on the frequency axis. Both these axes thus represent range in their respective Doppler systems. Second, if $\Delta D_{PW}=cT_w/2 = \Delta D_{FM}=cf_w/(2S_0)$, it can be shown analytically that the resulting axial range resolution distance is identical for the two systems.

The performance of the peak detection of the cross-correlation function can be evaluated by comparing the input signals to the cross-correlation and the cross-correlation function itself. With the above stated assumptions, analytical analysis of the signal-to-noise ratio (SNR) reveals that the SNR for the input signals in the PW–tsm Doppler system is identical to the SNR for the input spectra in the FM–fsm Doppler system. Finally, consider the behavior of the cross-correlation functions. In addition to the aforementioned values for $\Delta D_{PW}$ and $\Delta D_{FM}$, assume that a search window is applied to the cross-correlation functions, such that only velocities in the range of $\pm v_{\text{max}}$ can be detected. It can then be shown analytically that the cross-correlation functions with high probability will contain exactly one cycle within the search window, even though the real input waveforms to the cross-correlator behave differently for the PW–tsm and the FM–fsm Doppler systems. Thus there is very little risk of detecting a sidelobe in the cross-correlation function. The results show that performance of the two Doppler systems should be roughly the same.

In a practical implementation, the operating conditions
of the PW and FM Doppler systems may differ in several aspects. Due to the relationship between bandwidth and peak power in pulsed systems (assuming constant mean power), PW Doppler systems may not be able to utilize the full bandwidth afforded by the transducer whereas the bandwidth limitation of the FM Doppler system can be assumed to be that of the transducer; these factors may give the FM Doppler system a better axial resolution and improve the velocity estimate. In the measurement situations where a peak power limitation is encountered (e.g., due to cavitation and/or non-linearities) before a mean power limitation, the FM Doppler system can operate at a higher mean power level, thus giving an improved SNR relative to the PW Doppler system.

V. SIMULATION COMPARISONS

In order to provide a limited evaluation of the performance of the two Doppler systems, a few simulation results are presented.

A 2-D flow situation, simulating parabolic flow in a rigid tube, was modeled. The received signals were calculated from a large number of scattering particles, according to (11), randomly distributed inside the region from where backscattered signals would be received. The model includes both lateral variation in ultrasound beam intensity and velocity variation within the range cell. The scattering coefficient was chosen to be frequency independent.

The parameters common to both systems were as follows: \( f_0 = 5 \text{ MHz}, B_{\text{rms}} = 1.06 \text{ MHz}, \alpha = 3; D_{\text{max}} = 0.075 \text{ m}; T_r = 2D_{\text{max}}/c = 100 \mu s; v_{\text{alias}} = 0.75 \text{ m/s}. \) The maximal flow velocity in direction of the beam was \( v_{\text{max}} = 0.85v_{\text{alias}} = 0.64 \text{ m/s}. \) \( L = 2 \) and SNR = 20 dB. The shapes of the mean spectrum of the signal and the mean spectrum of the noise were identical (Gaussian).

The parameters for the PW Doppler system were: \( t_m,\text{PW} = 637 \text{ ns} = 3.2f_0 \) [obtained from \( B_{\text{rms}} = \alpha/(\sqrt{2\pi f_0 t_m,\text{PW}})], T_w = 8/f_0, \) giving \( \Delta D = cT_w/2 = 1.2 \text{ mm}. \)

The specific parameters for the FM Doppler system were: \( B_0 = 9 \text{ MHz} \) [obtained from \( B_{\text{rms}} = B_0/\sqrt{8\alpha} \)] which yields \( f_1 = 0.5 \text{ MHz} \) and \( f_2 = 9.5 \text{ MHz}; t_m,\text{FM} = 0.87T_r = 80 \mu s. \)

The result of 3000 independent repetitions of the simulations is given in Fig. 5(a) and (b) which shows the mean velocity profiles together with \( \pm 1 \) s.d. for the PW and FM Doppler systems, respectively. It was verified that doubling the number of repetitions and doubling the scatterer density did not change the results noticeably. As seen from these results, the two systems function nearly identically. The slightly better performance of the PW-tsm Doppler system may be due to sidelobes in the fsm spectrum.

VI. EXPERIMENTAL COMPARISON

This section presents the experimental system and the measured velocity profiles for the PW and FM Doppler systems. Note that the experimental results to be presented are included to give a mainly qualitative experimental proof of concept and should not be seen primarily as a verification of the analytical results.

![FIG. 5. Mean velocity profiles (-----) obtained with simulation model. The true velocity profile, TVP (---), (known a priori) is shown together with the velocity profiles obtained with the PW–tsm Doppler system in (a) and the FM–fsm Doppler system in (b). The results are obtained from 3000 independent profiles, each estimated with a signal-to-noise ratio of 20 dB. See text for additional parameters.](Image)
If for transmission and one ring for reception. By means of
the DSO, 32,000 eight-bit samples of the received signal
were subsequently recorded and stored. The sampling frequency
was set of 12.5 MHz, limiting the total observation time, $T_{obs}$, to 2.56 ms. The signal processing scheme was
done exclusively in the computer. A stationary echo canceler
(SEC) was included to remove stationary echoes.

The flow phantom is also shown in Fig. 6. A centrifugal
pump circulated a mixture of water and corn starch (2%–5%
vol.) from a reservoir. The water in the reservoir was stirred
with a magnetically driven stirring device in order to avoid
aggregation of the corn starch. The pump was controlled by
a variable voltage to obtain different flow rates. The tube segment, where the measurements were taken, consisted of
heat shrinking tubes of various diameters, suspended inside a
water-filled scanning tank. The tube diameters were selected
in such a way that they correspond to larger human arteries.
The tube was suspended vertically to achieve a symmetric
velocity profile and the flow was measured in the lower end
of this tube.

The systems parameters common for the two systems
are: $T_r = 80\,\mu s$, $D_{max} = 60\,mm$, $L = 32$ (number of transmitted
signals), and $c = 1500\,m/s$. The parameters for the transmit-
sed signal for the PW–tsm Doppler system were as follows:
$f_0 = 3.5\,MHz$, $t_m = 4/f_0$, $v_{alias} = c/(4f_0T_r) = 1.33\,m/s$. The
parameters for the transmitted signal for the FM–fsm Doppler
system were: $f_1 = 2.75\,MHz$, $f_2 = 4.75\,MHz$, $f_0 = 3.75\,MHz$,
$t_m = 60\,\mu s$, and $v_{alias} = c/(4f_0T_r) = 1.25\,m/s$. In both systems,
a rectangular envelope was used for the transmitted signals
sent from the AFG to the ultrasound transducer. The range
volume was $\Delta D_{PW} = \Delta D_{FM} = 2\,mm$ for a total of 29 range
cells. Both larger and smaller resolution cells were tried in
the signal processing, but without obtaining more precise
velocity estimates. Specifically, increasing the axial resolu-
tion distance (increasing $T_w$) yielded a poorer cross-
correlation function estimate as the range cell in this case
contained a larger velocity variation. On the other hand, lower-
ing $T_w$ gave shorter input signals to the cross-correlation
function, which also degraded the estimate. The “true” peak
in the discrete cross-correlation function was estimated from
a three-point parabolic fit around the peak value in the discrete cross-correlation function.

B. Performance of measurement system

In Sec. IV, the two Doppler systems were compared and
the performances were found to be roughly identical, assum-
ing the same bandwidth of the transmitted signal and the
same signal-to-noise ratio.

In the experimental system, the bandwidth of the trans-
mitted signals was evaluated and found to be slightly larger
for the FM Doppler system than for the PW Doppler system.
Furthermore, the spectra of the transmitted FM signals devi-
ated significantly from a Gaussian shape. Consequently, the
compensation/conversion parameter used in (28) is not valid.
A correction factor was empirically found to be 1.4, such
that the velocity estimates found from (28) had to be multi-
plied with 1.4 to yield the correct result.

The signal-to-noise ratio depends on several factors: The
level of energy transmitted, the background noise level, and
the dynamic range of the digitizing equipment. The back-
ground noise level was identical in the two Doppler system.
The transmitted energy, however, was much higher for the
FM Doppler system than for the PW Doppler system. How-
ever, as the background noise level was quite low, this ad-

dvantage in transmitted power did not carry any performance
improvement for the FM Doppler system over the PW Dop-
pler system. Furthermore, the FM Doppler system had a se-
rious drawback due to significant electric cross-talk in the
transducer which combined with the received signals from
the flow region. As a result, the output of the digital station-
ary echo canceler (SEC) was represented by only a few bits,
specifically, 7 bits for the PW Doppler system versus only 3
bits for the FM Doppler system. The corresponding signal-
to-noise ratios were approximately 44 and 20 dB, respec-
tively. These findings are consistent with the results in Table

\begin{figure}
\centering
\includegraphics[width=\textwidth]{fig6}
\caption{The experimental system. A centrifugal pump is circulating a mixture of water and corn starch. The pump is controlled by a variable voltage to
achieve different flow rates. The transmission signal is generated by the arbitrary function generator (AFG) which sends the signal to the power amplifier (PA).
The transmitting part of the transducer is connected to the power amplifier, while the receiving part is connected to the digital storage oscilloscope (DSO).
Both the AFG and the DSO are controlled from a personal computer via a GPIB (IEEE-488) bus.}
\end{figure}
I which shows the cross-correlation coefficient, \( r_{\text{meas}} \), in the actual situation. The level of \( r_{\text{meas}} \) is much lower for the FM case. Note that the cross-correlation coefficients at the peak value of the cross-correlation function, \( r_{nf} \), in the absence of cross talk and noise, are roughly identical in the two Doppler systems, as the measurement situations including PW and FM beam shapes were roughly the same.

### C. Velocity profiles

Since measurements on phantoms can never be accurately simulated, one fundamental problem arises: There is no reference velocity profile to which the experimental results can be compared. In order to be able to estimate the shape of the velocity profiles, the phantom was optimized mechanically to minimize flow perturbation. The velocities were chosen to represent typical velocities in the major arteries; this resulted in Reynolds numbers greater than or equal to 6000 for all the flow velocities in the experiments. It is here assumed, and supported by simple viscosity measurements, that the corn starch only produces minimal change in viscosity. Whereas Reynolds numbers in the region from roughly 2500 to 6000 (the upper limit is dependent on the tube smoothness and other experimental parameters) produce the so-called transition region flow which is chaotic and whose profile is not readily predictable, \( \text{flow at higher Reynolds numbers is characterized by a mean velocity profile which is approximately flat, although the corresponding instantaneous velocity profile exhibits significant random local fluctuations. The experimental results represent a mean velocity profile, as they are based on the average of 32 sweeps, corresponding to a time average over } 2.56 \text{ ms.} \)

In Fig. 7(a)–(c), velocity profiles are presented for the three different flow velocities listed in Table I. The velocity profiles are power-gated, i.e., when the power, after stationary echo canceling, in a given range cell falls below a pre-set threshold value, the detected velocity is set to zero for that range cell. The flow measurements were all carried out with the use of a simple stationary echo canceler. To investigate possible differences in behavior for PW and FM signals, we have modeled the transfer function of the stationary echo canceler as a function of flow velocity and bandwidth of the excitation signal, for both the PW and FM Doppler signals. The results showed that the transfer functions are very similar, albeit not identical, when realistic bandwidths are used.

![Figure 7](image-url)  
*Fig. 7. Measured velocity profiles for PW-tsm and FM-fsm Doppler systems. See Table I for parameter values.*

All the measured velocity profiles exhibit a reasonably good agreement with the directly measured volume flows. As the Reynolds numbers in all cases far exceed the limit for laminar flow, the mean velocity profiles are approximately flat, except near the tube walls, and with rapid local fluctuations, as has also been demonstrated with laser Doppler velocimetry and with bubble visualization. With respect to the width of the flow profiles, relative large variations could be seen near the location of the back wall which possibly may be due to attenuation by very small air bubbles across the tube. This variation makes it more difficult to verify the mean velocity.

### VII. DISCUSSION AND CONCLUSIONS

In this paper, a velocity profiling system based on the transmission of coherent repetitive frequency-modulated
sweep signal has been analyzed analytically, compared to the PW Doppler system utilizing time-shift measurements, and evaluated with simulations and experiments. A specific advantage of the FM Doppler system is the much lower peak power relative to the conventional PW Doppler systems. This FM–fsm Doppler system is based on cross-correlation of the real parts of consecutive so-called fsm spectra, analogous to the cross-correlation of consecutive received signal segments in a PW–tsm Doppler system. The flow velocity is estimated from the peak location in this cross-correlation function. As the peak can occur anywhere in the function, the PW–tsm and FM–fsm Doppler systems do not suffer from the aliasing phenomena, known from Doppler systems using phase shift measurement. On the other hand, under poor SNR conditions these new systems risk detecting one of the sidelobes in the cross-correlation function as the peak, thus providing an erroneous result. This problem may be circumvented by only searching for the peak in the region that corresponds exactly to the aliasing-free velocity range in a psm Doppler system. However, in this case, the cross-correlation-based Doppler systems function in the same way as the psm Doppler systems.

The factors determining the performance of the two systems were found to be very similar, arguing for a similar performance of the two systems. This is supported by the preliminary simulation results which show that under matched conditions (bandwidth and SNR), the two systems perform very similarly.

The feasibility of measuring flow profiles with the FM and PW Doppler systems on a simple flow model under semirealistic conditions has been demonstrated. In order to validate the applicability in the area of medical diagnostic ultrasound, experiments with a soft tissue-like coupling medium and in vivo experiments must be carried out.

Considering that the experimental system suffered from severe cross-talk for the FM–fsm measurements and therefore had insufficient dynamic range, combined with the fact that the shape of the transmitted signal envelope was very different from a Gaussian shape, the profiles obtained with the PW and FM Doppler systems nevertheless agree quite well. The PW–tsm and FM–fsm profiles appear reasonable and the reproducibility was quite good. This indicates that the flow phantom and the measurement system, as such, functioned properly.

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**APPENDIX A: DERIVATION OF \( \tilde{G}_a^{(n)}(f) \)**

In this Appendix, the demodulated signal, \( \tilde{g}_a^{(n)}(t) \), and its spectrum, \( \tilde{G}_a^{(n)}(f) \), are derived. From (13) we have for a single scatterer that

\[
\tilde{g}_a^{(n)}(t) = 2LP[\tilde{g}_r^{(n)}(t)\tilde{g}_r(t)] \\
= r e^{-\alpha_G t^2} e^{i\pi f_1(t-t_s) + \pi S_0(t-t_s)^2} \\
\times \frac{1}{2} \text{Re}[\exp(j[2\pi f_1(t-t_s) + \pi S_0(t-t_s)^2])], \\
0 \leq t \leq t_s + t_m. \tag{A1}
\]

Setting

\[
\theta = 2\pi f_1(t-t_s) + \pi S_0(t-t_s)^2, \\
\theta_{ref} = 2\pi f_1(t-t_s) + \pi S_0(t-t_s)^2
\]

we can write the terms being processed by the ideal low-pass filter as

\[
2LP(e^{i\theta}) = 2LP(e^{i\theta_{ref}}) \\
= 2LP\left(\cos(\theta) \right) \\
= \exp(j(\theta - \theta_{ref})), \tag{A2}
\]

so that

\[
\tilde{g}_a^{(n)}(t) = r e^{-\alpha_G t^2} e^{i\pi f_1(t-t_s)} + S_0(t^2 - (t_s)^2) + 2S_0(t-t_s)^2}, \\
0 \leq t \leq t_s + t_m. \tag{A3}
\]

To simplify the notation of (A4), the following terms will be defined:

\[
t_d^{(n)} = t_s + t_m, \\
a_{\text{env}}^{(n)}(t) = e^{-\alpha_G t^2} e^{i\pi f_1(t-t_s)} + S_0(t^2 - (t_s)^2), \\
A_{\text{env}}^{(n)}(t) = e^{-\alpha_G t^2} e^{i\pi f_1(t-t_s)} + S_0(t^2 - (t_s)^2). \tag{A5}
\]

In (A5), \( A_{\text{env}}^{(n)}(t) \) is a constant amplitude term, \( a_{\text{env}}^{(n)}(t) \) represents the envelope function of \( \tilde{g}_a^{(n)}(t) \), and \( \varphi_a^{(n)} \) describes a constant phase term. By means of these terms, (A4) can be expressed as follows:

\[
\tilde{g}_a^{(n)}(t) = A_{\text{env}}^{(n)}(t) e^{-2\pi S_0 f_1 t_d^{(n)}} + j\varphi_a^{(n)}. \tag{A6}
\]

As \( \tilde{g}_a^{(n)}(t) \) only physically exists for \( t \geq t_s \) due to the \( t_s \) seconds delay of the demodulating sweep signal, it is appropriate to use \( t = t_s \) as the zero time reference when calculat-
ing $\tilde{G}_d^{(n)}(f)$. In other words, the spectrum of $\tilde{g}_d^{(n)}(t+s)$ is to be found where

$$\tilde{g}_d^{(n)}(t+s) = A_0^{(n)} a_{En}^{(n)}(t+s) \exp[j 2\pi S(t+s)_d^{(n)} + j\varphi_a^{(n)}].$$

(A7)

Before doing that, (A7) will be simplified further. Through straightforward arithmetic manipulation, it can be shown that

$$A_0^{(n)} a_{En}^{(n)}(t+s) = r \exp\left[-\alpha_G\left(t_d^{(n)} + \frac{t_m}{2}\right)^2\right] \times \exp\left[-\alpha_G t^2 + 2\alpha_G\left(t_d^{(n)} + \frac{t_m}{2}\right)t\right].$$

(A8)

By defining the following two new terms:

$$B_0^{(n)} = r \exp\left[-\alpha_G\left(t_d^{(n)} + \frac{t_m}{2}\right)^2\right]$$

and

$$\varphi_b^{(n)} = \pi t_d^{(n)} (2 f_1 - S_0 t_d^{(n)}),$$

the complex spectrum of this signal, $\tilde{G}_a^{(n)}(f)$, can be found as

$$\tilde{G}_a^{(n)}(f) = \int_{-\infty}^{\infty} \tilde{g}_d^{(n)}(t+s) e^{-j2\pi ft} dt$$

$$= B_0^{(n)} \exp[j\varphi_b^{(n)}] \int_{-\infty}^{\infty} \exp\left[-\alpha_G t^2\right]$$

$$- \left[-2\alpha_G\left(t_d^{(n)} + \frac{t_m}{2}\right) - j2\pi(S_0 t_d^{(n)} - f)\right] dt.$$  

(A10)

A closed form solution to (A10) can be obtained from the following integral solution:

$$\int_{-\infty}^{\infty} \exp(-\beta x^2 - \gamma x) dx = \frac{\sqrt{\pi}}{\beta} \exp(\gamma^2/4\beta^2), \quad \text{Re}(\beta) > 0.$$  

(A11)

Using (A11), (A10) can be written in analytical form as

$$\tilde{G}_a^{(n)}(f) = B_0^{(n)} \sqrt{\frac{\pi}{\alpha_G}} \exp[j\varphi_b^{(n)}]$$

$$\times \exp\left[\left[-2\alpha_G(t_d^{(n)} + t_m/2) - j2\pi(S_0 t_d^{(n)} - f)\right]^2\right]/4\alpha_G.$$  

(A12)

Collecting terms and introducing

$$f_d^{(n)} = t_d^{(n)} - \tau_0 = (t^{(n)} - t_s) S_0 = \frac{2(d^{(n)} - D)}{c} S_0,$$  

(A13)

which is the center frequency of the spectrum (or the so-called position frequency of the fsm spectrum) makes it possible to write (A12) as

$$\tilde{G}_a^{(n)}(f) = \sqrt{\frac{\pi}{\alpha_G}} B_0^{(n)} \exp[j\varphi_b^{(n)}] \exp\left[\alpha_G f_d^{(n)} + f_m^{(n)}\right]^2\right]$$

$$\times \exp\left[-\frac{\pi^2}{\alpha_G} (f_d^{(n)} - f)^2 + j2\pi(t_d^{(n)} + t_m)\right]$$

$$\times (f_d^{(n)} - f).$$  

(A14)

It is readily seen from (A9) that $B_0^{(n)} \exp[\alpha_G(t_d^{(n)} + t_m/2)^2]$ evaluates to the reflection coefficient, $r$. We can thus finally write (A15) as

$$\tilde{G}_a^{(n)}(f) = r \sqrt{\frac{\pi}{\alpha_G}} \exp\left[-\frac{\pi^2}{\alpha_G} (f_d^{(n)} - f)^2\right]$$

$$\times \exp\left[j2\pi(t_d^{(n)} + t_m)(f_d^{(n)} - f) + j\varphi_b^{(n)}\right].$$  

(A15)

**APPENDIX B: DERIVATION OF THE COMPLEX CORRELATION FUNCTION $\tilde{C}_{FM}^{(n,n+1)}(\gamma)$**

The formulation of the cross-correlation function is given in (21) as follows:

$$\tilde{C}_{FM}^{(n,n+1)}(\gamma) = \int_{-\infty}^{\infty} \tilde{G}_a^{(n)}(f) \overline{\tilde{G}_a^{(n+1)}(f + \gamma)} df.$$  

(B1)

Inserting the result from (A15) gives

$$\tilde{C}_{FM}^{(n,n+1)}(\gamma) = r^2 \int_{-\infty}^{\infty} \sqrt{\frac{\pi}{\alpha_G}} \exp\left[-\frac{\pi^2}{\alpha_G} (f_d^{(n)} - f)^2\right]$$

$$\times \exp\left[j2\pi(t_d^{(n)} + t_m)(f_d^{(n)} - f) + j\varphi_b^{(n)}\right]$$

$$\times \sqrt{\frac{\pi}{\alpha_G}} \exp\left[-\frac{\pi^2}{\alpha_G} (f_d^{(n+1)} - f - \gamma)^2\right]$$

$$\times \exp\left[j2\pi(t_d^{(n+1)} + \tau_0 + t_m)\right]$$

$$\times \overline{(f_d^{(n+1)} - f - \gamma) - j\varphi_b^{(n+1)}} df.$$  

(B2)

where $\tau_0 = t_d^{(n+1)} - t_d^{(n)} = (2\nu T_s)/c$ is introduced, giving $t_d^{(n+1)} - t_s = t_d^{(n)} + \tau_0$. Here, $\tau_0$ represents the change in round-trip travel time to the scatterer from one emitted sweep to the next.

Introducing $\Delta f_d = f_d^{(n+1)} - f_d^{(n)} = 2\nu T_s/c = \tau_0 S_0$, as defined in (18), $\gamma = \Delta f_d - \gamma$, and $f^{(n)} - f$ allows (B2) to be written as

$$\tilde{C}_{FM}^{(n,n+1)}(\Delta f_d - \gamma)$$

$$= r^2 \sqrt{\frac{\pi}{2\alpha_G}} \exp\left[-\frac{\alpha_G \tau_0}{2}\right] \exp\left[-\frac{\pi^2}{2\alpha_G} \gamma^2\right]$$

$$\times \exp[-j \pi(2t_d^{(n+1)} + \tau_0 + t_m)\gamma' + j(\varphi_b^{(n+1)} - \varphi_b^{(n+1)})].$$  

(B3)

Define
Equations and associated with the approximated expressions for the peak must be made. To justify the approximations, the errors as-
small.

In this Appendix, an expression is derived for the loca-

Re

\[ \varphi(n) = \varphi(n) \]

Equations (B4), (B5), and (B6) make it possible to write (B3) as

\[ C_{\text{FM}}^{(n,n+1)}(\gamma) = A_C \exp \left[ \frac{-\pi^2}{2\alpha G} (\Delta f_a - \gamma)^2 \right] \times \exp[ -j\pi t_a^{(n)}(\Delta f_a - \gamma) + j\varphi(n)] \]  

\[ \text{(B7)} \]

APPENDIX C: LOCATION OF PEAK IN C_{\text{FM}}^{(n,n+1)}(\gamma)

In this Appendix, an expression is derived for the location of the peak in the real part of \( C_{\text{FM}}^{(n,n+1)}(\gamma) \) which is the complex cross-correlation function of consecutive FSM spectra. The real part of \( C_{\text{FM}}^{(n,n+1)}(\gamma) \) is

\[ \text{Re}(C_{\text{FM}}^{(n,n+1)}(\gamma)) = A_C \exp \left[ -\pi^2 \frac{2\alpha G}{(\Delta f_a - \gamma)^2} \right] \times \cos[ -\pi t_a^{(n)}(\Delta f_a - \gamma) + \varphi(n)] \]  

\[ \text{(C1)} \]

For ease of notation, the following terms are introduced:

\[ f(\gamma) = \frac{1}{A_C} \text{Re}(C_{\text{FM}}^{(n,n+1)}(\gamma)), \quad A = \frac{\pi^2}{2\alpha G}, \]

\[ B = \pi t_a^{(n)}, \quad C = \varphi(n), \]  

\[ \text{(C2)} \]

where \( \varphi(n) \) is given in (B6). Equation (C1) can now be written as

\[ f(\gamma) = \exp[ -A(\Delta f_a - \gamma)^2] \cos[ -B(\Delta f_a - \gamma) + C]. \]  

\[ \text{(C3)} \]

Let \( \gamma_0 \) be the value of \( \gamma \) at which \( f(\gamma) \) has a maximum, or equivalently, \( f(\gamma)=0 \). Setting \( f(\gamma_0)=0 \) yields

\[ B(\Delta f_a - \gamma_0) - C = -\arctan \left( \frac{2A}{B}(\Delta f_a - \gamma_0) \right). \]  

\[ \text{(C4)} \]

In order to solve and simplify (C4), several approximations must be made. To justify the approximations, the errors associated with the approximated expressions for the peak location will subsequently be evaluated, based on the correct peak location specified in (C1), and shown to be acceptably small.

The first approximation is a linearization of (C4). The maximum value of the argument to the arctan function is

\[ \max \left( \frac{2A}{B}(\Delta f_a - \gamma_0) \right) \cong \frac{\pi t_m}{2\alpha^2} \max(\Delta f_a - \gamma_0) \]  

\[ \cong \frac{\pi t_m}{2\alpha^2} \frac{S_0}{2f_1} = \frac{\pi}{4\alpha^2} \cong 0.09. \]  

\[ \text{(C5)} \]

The following approach is used in evaluating (C5): \( \max(\Delta f_a - \gamma_0) < \max(\Delta f_a) = (2T_S/c)v_{\text{alias}} = (S_0/2f_1) \), where the term \( \max(\Delta f_a - \gamma_0) \) represents the maximum difference between the peak locations in the magnitude and real part of the cross-correlation function. In addition, \( B_0 = f_0 \) and \( \alpha = 3 \). From (C5) it is seen that the upper bound of the argument is sufficiently small for (C4) to be linearized. This means that (C4) can be approximated to

\[ B(\Delta f_a - \gamma_0) - C \cong -\frac{2A}{B}(\Delta f_a - \gamma_0) \]  

\[ \text{(C6)} \]

giving

\[ \gamma_0 \geq \frac{BC}{2A + B^2}. \]  

\[ \text{(C7)} \]

\( \Delta f_a \) is the spectral shift observed in the magnitude spectra, thus the term \( \frac{BC}{2A + B^2} \) gives the correction to this spectral shift. By using that \( t_a^{(n)} = t_a^{(n)} + t_m = t_a^{(n)} + t_m \), \( t_m = T_r \) and that \( S_0T_r - 2f_1 = (T_r/T_m)B_0 - 2f_1 \equiv -2f_1 \) (as \( T_m \ll 1 \)), the following simplification can be made:

\[ \frac{BC}{2A + B^2} \equiv \frac{\pi t_a^{(n)}}{\pi^2 / \alpha G + (\pi t_a^{(n)})^2} \equiv \frac{2t_a^{(n)} + t_m}{(2t_a^{(n)} + t_m)^2 + 1 / \alpha G}. \]  

\[ \text{(C8)} \]

By further assuming that

\[ \frac{B_0}{f_1} \frac{t_a^{(n)}}{t_m} \ll 1; \quad \frac{2t_a^{(n)}}{t_m} \ll 1; \quad \frac{1}{2\alpha^2} \ll 1, \]  

\[ \text{(C9)} \]

(C8) can finally be simplified to

\[ \frac{2f_1}{t_m} \frac{c}{c} T_r. \]  

\[ \text{(C10)} \]

By use of (C10), (C7) can be written as

\[ \gamma_0 \geq \frac{2vT_r}{c} \left( S_0 + \frac{2f_1}{t_m} \right). \]  

\[ \text{(C11)} \]

Eventually, the velocity can be found from (C11) as

\[ \hat{v} \cong \frac{T_r}{c} \left( S_0 + \frac{2f_1}{t_m} \right). \]  

\[ \text{(C12)} \]

In order to quantify the error committed with the two levels of approximations, a simulation program was used to find the correct peak from (C1) and compare this with the two results in (C7) and (C11). Using the following parameters: \( \alpha = 3; \ c = 1500 \text{ m/s}; \ D_{\text{max}} = 0.1 \text{ m}; \ T_r = 2D_{\text{max}}/c = 113 \mu s; \ D = D_{\text{max}} / 2; \ \text{d} = D; \ f_0 = 3.5 \text{ MHz}; \ B_0 = 5 \text{ MHz}; \ t_m = 0.8T_r \), resulted in a relative error that was less than 0.1% and 1.6% for (C7) and (C11), respectively, when evaluated over \( [-v_{\text{alias}}, v_{\text{alias}}] \). These figures are much smaller.
than errors normally associated with ultrasonic blood flow measurement.