

2016 4th International Workshop on Compressed Sensing Theory and its Applications to Radar, Sonar and Remote Sensing (CoSeRa 2016)

**Aachen, Germany
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Monday, September 19

Monday, September 19, 15:00 - 16:30

Tutorial - Part I

A guided tour of algorithms for sparse recovery

Sparsity is a very powerful prior for the identification of signals from noisy indirect measurements. The recovery of the signal is usually performed by suitable linearly constrained optimizations with additional sparsity enforcing convex or nonconvex objective functions. Depending on the specific formulation, one can produce a variety of different algorithms. In this tutorial the numerical realizations of such linear and nonlinear programs are reviewed and compared with respect to different noisy scenarios. With the intention of providing a useful guide to users, we provide a sound mathematical introduction with rigorous derivations and proofs of convergence of all algorithms and we illustrate in detail their behaviour by extensive numerical experiments. (Massimo Fornasier (TU Munich, Germany))

Monday, September 19, 16:30 - 16:45

Coffee Break

Monday, September 19, 16:45 - 18:15

Tutorial - Part II

A guided tour of algorithms for sparse recovery

Monday, September 19, 18:15 - 19:30

Welcome Reception

Tuesday, September 20

Tuesday, September 20, 08:45 - 09:00

Opening

Tuesday, September 20, 09:00 - 10:00

Keynote I

Sparse signal separation and imaging in Synthetic Aperture Radar

Synthetic Aperture Radar offers the capability of all-weather, day-or-night remote imaging. Since its first development in the 1950s researchers have sought to advance the technology to encompass more advanced

imaging applications, including foliage penetrating radar, volumetric and dynamic imaging. Such applications present significant technological challenges including the problem of severe undersampling. This talk will describe work we have done at the University of Edinburgh in conjunction with the UK Defence Science and Technology Laboratories (Dstl) to develop advanced compressed sensing inspired solutions for airborne low frequency SAR imaging and to a new approach for moving target and background signal separation and imaging in multi-channel SAR. (Mike Davies (University of Edinburgh, United Kingdom))

Tuesday, September 20, 10:00 - 11:00

A.1: Mathematical CS Tools

Chair: Laurent Jacques (University of Louvain, Belgium)

***Recursive Enhancement of Intrinsic Soft Information for Complex Reed-Solomon Codes* 1**

Mostafa H. Mohamed, Henning Zörlein and Martin Bossert (Ulm University, Germany)

***A Dual-Deconvolution Algorithm for Radar and Communication Black-Space Spectrum Sharing* 6**

Masoud Farshchian (Empyrean Waves, LLC, USA); Ivan Selesnick (New York University, USA)

***Off the Grid Time Delay Estimation for Sparse Translation-Invariant Signals* 11**

Yongsung Park, Woojae Seong and Youngmin Choo (Seoul National University, Korea)

Tuesday, September 20, 11:00 - 11:30

Coffee Break

Tuesday, September 20, 11:30 - 12:50

A.2: Mathematical Analysis of CS (Invited)

Chair: Holger Rauhut (RWTH Aachen, Germany)

***A Non-Convex Blind Calibration Method for Randomised Sensing Strategies* 16**

Valerio Cambarelli (Université Catholique de Louvain, Belgium); Laurent Jacques (Université Catholique de Louvain)

***Generalized Line Spectral Estimation for Radar and Localization* 21**

Reinhard Heckel (University of California, Berkeley, USA); Mahdi Soltanolkotabi (University of Southern California, USA)

***Blind deconvolution and Compressed Sensing* 24**

Dominik Stöger (Technical University of Munich, Germany); Peter Jung (TU-Berlin, Communications and Information Theory Group & Fraunhofer HHI - Heinrich Hertz Institute, Germany); Felix Krahmer (Technische Universität München, Germany)

Estimation of the Scattering Function of Overspread Radar Targets N/A
Götz Pfander (Uni. Marburg, Germany); Pavel Zheltov (Palantir Technologies, USA)

Tuesday, September 20, 12:50 - 14:00

Lunch Break

Tuesday, September 20, 14:00 - 15:40

A.3: Imaging

Chair: Michael Davis (Georgia Institute of Technology, USA)

Super Resolution of Synthetic Aperture Radar Data By Convex Optimization 28
Filippo Biondi (University of L'Aquila & Italian Ministry of Defence, Italy)

A Procedure for Optimal Pulse Selection Strategy in Radar Imaging Systems 33
Miloš Daković and Ljubisa Stankovic (University of Montenegro, Montenegro);
Srdjan Stanković (Faculty of Electrical Engineering, University of Montenegro,
Montenegro)

Multi-channel SAR Covariance Matrix Estimation Based on Compressive Covariance Sensing 37
Zhe Zhang (The George Washington University & George Mason University, USA);
Zhi Tian (George Mason University, USA); Bingchen Zhang (Institute of Electronics,
Chinese Academy of Sciences, P.R. China); Wen Hong (National Key Laboratory of
Microwave imaging Technology & Institute of Electronics, Chinese Academy of
Sciences, P.R. China); YiRong Wu (National Key Laboratory of Microwave Imaging
Technology, P.R. China); Li Li (China Agricultural University, P.R. China)

OFDM SAR Multiple Targets Image Reconstruction using MUSIC-LSE Algorithm 42
Mohammed D Buhari (Newcastle University & ATBU Bauchi Nigeria, United
Kingdom); Guiyun Tian, Rajesh Tiwari and Ruslee Sutthaweekul (Newcastle
University, United Kingdom); Ali H Muqaibel (KFUPM, Saudi Arabia)

Multi-circular synthetic aperture radar imaging processing procedure based on compressive sensing 47
Qian Bao and Yun Lin (Institute of Electronics, Chinese Academy of Sciences, P.R.
China); Wen Hong (National Key Laboratory of Microwave imaging Technology &
Institute of Electronics, Chinese Academy of Sciences, P.R. China); Bingchen Zhang
(Institute of Electronics, Chinese Academy of Sciences, P.R. China)

Tuesday, September 20, 15:40 - 16:10

Coffee Break

Tuesday, September 20, 16:10 - 17:50

A.4: Hardware + Tracking

Chair: Radmila Pribić (Thales Nederland BV Delft, The Netherlands)

Maritime Vehicle Tracking Using Underwater Gliders and Particle Filters 51

Ioannis Kyriakides and Ehsan Abdi (University of Nicosia, Cyprus); Daniel Hayes (University of Cyprus, Cyprus)

Cognitive Sub-Nyquist Hardware Prototype of a Collocated MIMO Radar 56

Kumar Vijay Mishra, Eli Shoshan, Moshe Namer, Maxim Meltsin, David Cohen, Ron Madmoni, Shahar Dror and Robert Ifraimov (Technion - Israel Institute of Technology, Israel); Yonina C. Eldar (Technion-Israel Institute of Technology, Israel)

Online Blind Deconvolution for Sequential Through-the-Wall-Radar-Imaging 61

Hassan Mansour (Mitsubishi Electric Research Laboratories, USA); Ulugbek S. Kamilov (Mitsubishi Electric Research Laboratories (MERL), USA); Dehong Liu and Philip Orlik (Mitsubishi Electric Research Laboratories, USA); Petros T Boufounos (Mitsubishi Electric Research Laboratories); Kieran Parsons and Anthony Vetro (Mitsubishi Electric Research Laboratories, USA)

False Alarms in Radar Detection within Sparse-signal Processing 66

Radmila Pribić (Thales Nederland BV Delft, The Netherlands); Han Lun Yap (DSO National Laboratories, Singapore)

Bird Body and Wing-Beat Radar Doppler Signature Separation using Sparse Optimization 71

Masoud Farshchian (Empyrean Waves, LLC, USA); Ivan Selesnick (New York University, USA); Ankit Parekh (NYU Tandon School of Engineering, USA)

Wednesday, September 21

Wednesday, September 21, 09:00 - 10:40

A.5: Sparse Reconstruction in Remote Sensing (Invited)

Chair: Ludger Prünte (Fraunhofer-Institut für Hochfrequenzphysik und Radartechnik FHR, Germany)

Low Rank Plus Sparse Decomposition of Synthetic Aperture Radar Data For Maritime Surveillance 75

Filippo Biondi (University of L'Aquila & Italian Ministry of Defence, Italy)

***Simple Adaptive Progressive Edge-Growth Construction of LDPC Codes for Close(r)-to-Optimal Sensing in Pulsed ToF* 80**

Miguel Heredia Conde (Center for Sensorsystems (ZESS), University of Siegen, Germany); Klaus Hartmann (University of Siegen, Germany); Otmar Loffeld (Center for Sensorsystems (ZESS), University of Siegen, Germany)

***Compressed Sensing for the detection of moving targets from short sequences of pulses* 85**

Ludger Prünte (Fraunhofer-Institut für Hochfrequenzphysik und Radartechnik FHR, Germany)

***Compressive Sensing and Generalized Likelihood Ratio Test in SAR Tomography* 90**

Gianfranco Fornaro (CNR-IREA, Italy); Antonio Pauciuolo (IREA, CNR, Italy); Diego Reale (CNR-IREA, Italy); Matthias Weiß (Fraunhofer FHR, Germany); Alessandra Budillon (University of Naples Parthenope, Italy); Gilda Schirinzi (Università di Napoli Parthenope, Italy)

***Towards single-pixel FMCW radar reconstruction* 95**

Benjamin Fürsich (Technische Universität München & Signal Processing in Earth Observation (SiPEO), Germany); Richard Bamler (German Aerospace Center (DLR), Germany); Sven Augustin (Humboldt Universität zu Berlin & German Aerospace Center (DLR) Berlin, Germany); Heinz-Wilhelm Huebers (DLR Institute of Planetary Research, Germany); Xiao Xiang Zhu (German Aerospace Center (DLR), Remote Sensing Technology & Technical University of Munich (TUM), Signal Processing in Earth Observation, Germany)

Wednesday, September 21, 10:40 - 11:10

Coffee Break

Wednesday, September 21, 11:10 - 12:30

A.6: Sparse Sensing in Radar (Invited)

Chair: Athina Petropulu (Rutgers, The State University of New Jersey, USA)

***Compressive Spectrum Sensing with Spectral Priors for Cognitive Radar* 100**

Ali Koochakzadeh, Heng Qiao and Piya Pal (University of Maryland, College Park, USA)

***Coherent Distributed Array Imaging under Unknown Position Perturbations* 105**

Dehong Liu (Mitsubishi Electric Research Laboratories, USA); Ulugbek S. Kamilov (Mitsubishi Electric Research Laboratories (MERL), USA); Petros T Boufounos (Mitsubishi Electric Research Laboratories & Rice University, USA)

***On the Dimensionality of Wall and Target Return Subspaces in Through-the-Wall Radar Imaging* 110**

Zhihui Zhu and Michael Wakin (Colorado School of Mines, USA)

Weighted Sparse Bayesian Learning (WSBL) for Basis Selection in Linear Underdetermined Systems 115

Ahmed Al Hilli (Rutgers University & Al Furat Al-Awsat Technical University, Iraq., USA); Athina Petropulu (Rutgers, The State University of New Jersey, USA); Laleh Najafizadeh (Rutgers University, USA)

Wednesday, September 21, 12:30 - 13:40

Lunch Break

Wednesday, September 21, 13:40 - 14:40

Keynote II

Compressive Imaging and Resolution

While compressed sensing theory is discrete and linear, imaging models are typically continuous and nonlinear. Proper discretization must consider the representation and the sampling schemes in light of the resolution limit. In some cases, new sparse reconstruction methods are needed to treat the transition from discrete to continuous models. This talk reviews compressive techniques for achieving the resolution limit and discusses examples of super-resolution and multiple scattering imaging. (Albert Fannjiang (University of California, Davis, USA))

Wednesday, September 21, 14:40 - 15:50

A.7-I: Poster: Imaging

Chair: Ludger Prünte (Fraunhofer-Institut für Hochfrequenzphysik und Radartechnik FHR, Germany)

Compressive Tomographic Radar Imaging with Total Variation Regularization 120

Dehong Liu (Mitsubishi Electric Research Laboratories, USA); Ulugbek S. Kamilov (Mitsubishi Electric Research Laboratories (MERL), USA); Petros T Boufounos (Mitsubishi Electric Research Laboratories & Rice University, USA)

An Effective and Efficient Long-time Coherent Integration Method for Highly Maneuvering Radar Target in Sparse Domain 124

Xiaolong Chen and Xiaohan Yu (Naval Aeronautical and Astronautical University, P.R. China); Jian Guan (Naval Aeronautical Engineering Institute, P.R. China); You He (Naval Aeronautical and Astronautical University, P.R. China)

The Hybrid Cramér-Rao Bounds on Elevation in Compressive Sensing SAR Tomography 128

B. Yang, Xu and Y. You (Beihang University, P.R. China); X. Xie (Northwest A&F University, P.R. China)

CFAR Detection for the Complex Approximated Message Passing Reconstructed SAR Image 133

Hui Bi (Institute of Electronics, Chinese Academy of Sciences, P.R. China); Bingchen Zhang (Institute of Electronics, Chinese Academy of Science, P.R. China); Xiao Xiang Zhu (German Aerospace Center (DLR), Remote Sensing Technology &

Technical University of Munich (TUM), Signal Processing in Earth Observation, Germany); Wen Hong (National Key Laboratory of Microwave imaging Technology & Institute of Electronics, Chinese Academy of Sciences, P.R. China); YiRong Wu (National Key Laboratory of Microwave Imaging Technology, P.R. China)

Autofocus Algorithm for Radar / Sonar Imaging by Exploiting the Continuity Structure 138

Lu Wang (Northwestern Polytechnical University, P.R. China); Lifan Zhao (Nanyang Technological University, Singapore); Xiangyang Zeng and Qiang Wang (Northwestern Polytechnical University, P.R. China); Jiang Qian (UESTC, P.R. China); Guoan Bi (Nanyang Technological University, Singapore)

A.7-II: Poster: CS for Multi-Target and Multistatic

Chair: Matthias Weiß (Fraunhofer FHR, Germany)

Decentralized Multi-Agent Entropy-Driven Exploration under Sparsity Constraints 143

Christoph Manß and Dmitriy Shutin (German Aerospace Center (DLR), Germany); Thomas Wiedemann (German Aerospace Center, Germany); Alberto Viseras Ruiz (German Aerospace Center (DLR), Germany); Joachim Mueller (German Aerospace Center, Germany)

Multi-Target Super-Resolution Using Compressive Sensing Arguments for Multipath Interference Recovery 148

Xuan Vinh Nguyen and Otmar Loffeld (Center for Sensorsystems (ZESS), University of Siegen, Germany); Klaus Hartmann (University of Siegen, Germany)

Single Frequency Surveillance Radar Network using an adapted L1 Minimization Approach for Extended Targets 153

Matthias Weiß (Fraunhofer FHR, Germany)

Multiple Target Tracking Using Thermal Imaging and Radar Sensors 158

Ioannis Kyriakides (University of Nicosia, Cyprus)

Separation of Chirp Scattered Returns from a Mixture of Sinusoidal Tones in Noise 163

Masoud Farshchian (Empyrean Waves, LLC, USA); Ivan Selesnick (New York University, USA)

A.7-III: Poster: Sparse Reconstruction Aspects

Chair: Joachim H. G. Ender (Fraunhofer FHR & Universität Siegen, Germany)

Stochastic Resolution Analysis via a GLR Test in Radar 168

Radmila Pribić (Thales Nederland BV Delft, The Netherlands)

Adaptive Sub-Nyquist Sampling Based on Haar Wavelet and Compressive Sensing in Pulsed Radar 173

Assem Assem and Richard Dansereau (Carleton University, Canada); Fathy Ahmed (Military Technical College, Egypt)

Simplified Chirp Dictionary for Time-Frequency Signature Sparse Reconstruction of Radar Returns 178

Nguyen Yen (University of Leeds, Vietnam & Electronics and Electrical, unknown); Desmond McLernon (The University of Leeds, United Kingdom); Mounir Ghogho (University of Leeds & International University of Rabat, United Kingdom)

Compressive Sensing in Pulse Radar using Prior Information 183

Assem Assem and Richard Dansereau (Carleton University, Canada)

Compressive Sensing for Very High Frequency Radar With Application to Low-Angle Target Tracking Under Multipath Interference 188

Yuan Liu and Bo Jiu (National Laboratory of Radar Signal Processing, Xidian University); Hongwei Liu (National Laboratory of Radar Signal Processing, P.R. China); Lei Zhang (National Laboratory of Radar Signal Processing, Xidian University, P.R. China); Yongbo Zhao (National Laboratory of Radar Signal Processing, P.R. China)

Wednesday, September 21, 15:50 - 17:30

A.8: Antenna and DOA Estimation

Chair: Gianfranco Fornaro (CNR-IREA, Italy)

Direction of Arrival Estimation for Quasi-Stationary Signals using Nested Circular Array 193

Thomas Basikolo, Koichi Ichige and Hiroyuki Arai (Yokohama National University, Japan)

Single-snapshot DoA Estimation using Adaptive Elastic Net in the Complex Domain 197

Muhammad N Tabassum and Esa Ollila (Aalto University, Finland)

On Pre-Whitening and Accuracy in DOA Estimation by Sparse Signal Processing on Beamformed Data 202

Dave Bekers (TNO); Wim Lambertus van Rossum and Sebastiaan Jacobs (TNO, The Netherlands); Matijs Heiligers (TNO); Laura Anitori (TNO, The Netherlands); Emiel Stolp (Thales Nederland BV, The Netherlands); Lorenzo Cifola (Thales Nederland BV); Martin Podt (Thales Nederland BV, The Netherlands)

Optimum Linear Array Geometry with Minimum Redundancy for 2q-th Order Cumulant-Based Array Processing 207

Yuki Iizuka and Koichi Ichige (Yokohama National University, Japan)

Fast Antenna Characterization via a Sparse Spherical Multipole Expansion 212

David Löschenbrand and Christoph F Mecklenbräuker (Vienna University of Technology, Austria)

Wednesday, September 21, 19:00 - 23:00

Conference Dinner

Thursday, September 22

Thursday, September 22, 09:00 - 10:40

A.9: ISAR (Invited)

Chair: Marco Martorella (University of Pisa, Italy)

A Comparison of Compressive Sensing and Fourier Reconstructions for Radar Target Recognition 217

David Blacknell (DSTL, United Kingdom)

Analysis of Noise and Nonsparsity in the ISAR Image Recovery from a Reduced Set of Data 222

Ljubisa Stankovic, Isidora Stankovic and Miloš Daković (University of Montenegro, Montenegro)

ISAR Resolution Enhancement via Compressive Sensing: a Comparison with state of the art SR Techniques 227

Alessio Bacci (CNIT & University of Pisa, Italy); Elisa Giusti, Davide Cataldo, Sonia Tomei and Marco Martorella (University of Pisa, Italy)

ISAR Imaging Using a Null Space L1 Minimizing Kalman Filter Approach 232

Ling Wang (Nanjing University of Aeronautics and Astronautics, P.R. China); Otmar Loffeld (Center for Sensorsystems (ZESS), University of Siegen, Germany)

Compressive Sensing Methods for Radar Cross Section ISAR Measurements 237

Christer Larsson (Lund University & Saab Dynamics, Sweden)

Thursday, September 22, 10:40 - 11:10

Coffee Break

Thursday, September 22, 11:10 - 12:30

A.10: Special Aspects

Chair: Emre Ertin (The Ohio State University, USA)

Sub-Nyquist Radar with Optimized Sensing Matrices - Performance Evaluation Based on Simulations and Measurements 242

Hannes Stahl and Jan Mietzner (Airbus Defence & Space, Germany); Martin Kirscht (Airbus Defence and Space, Germany); Robert F.H. Fischer (Ulm University, Germany)

Compressive Space-Time Adaptive Processing Airborne Radar with Random Pulse Repetition Interval and Random Arrays 247

Zhaocheng Yang, Guihua Quan, Yuanbin Ma and Jianjun Huang (Shenzhen University, P.R. China)

Recovery Guarantees for High Resolution Radar Sensing with Compressive Illumination 252

Nithin Sugavanam, Siddharth Baskar and Emre Ertin (The Ohio State University, USA)

Combined based on Minimum Distance Orthogonal Matching Pursuit Method for Support Recovery Improvement in Super-Resolution Compressed Sensing 257

Xuan Vinh Nguyen and Otmar Loffeld (Center for Sensorsystems (ZESS), University of Siegen, Germany); Klaus Hartmann (University of Siegen, Germany)

Thursday, September 22, 12:30 - 13:40

Lunch Break

Thursday, September 22, 13:40 - 14:40

Keynote III

Compressive Sensing and the Real World of Sensors

The original theory of compressive sensing (CS) emphasizes the perfect reconstruction of the unknown sparse coefficient vector given a reduced number of linear measurements. Under these conditions, CS offers a great variety of theorems, algorithms and criteria for the sensing matrix to guarantee recovery.

While this discrete CS model is appropriate for image processing, encoding and decoding, it differs considerably from the real world of sensors. Especially the positions of sources are normally continuously distributed and don't lie on a grid. This often is called the 'off-grid problem'. But it is not a problem of the sources not to keep with the demands of CS to be located on the grid points, it is a problem of the wrong model of the real world.

This will be addressed in the presentation; ways are shown to sparse recovery closer to the real world. We will further discuss the 'random projection' approach, which is nice for the establishment of theorems, but by far not the most efficient way to get good results. (Joachim Ender (Fraunhofer FHR, Germany))

Thursday, September 22, 14:40 - 15:00

Closing Remarks