

Contents

<i>Contributors</i>	xx
<i>Preface</i>	xxi
1. An Introduction to Radar	1.1
1.1 Description of Radar	1.1
Radar Block Diagram	1.2
1.2 Radar Equation	1.6
Tracking	1.8
Volume Search	1.8
Jamming	1.9
Clutter	1.10
1.3 Information Available from the Radar Echo	1.10
Range	1.11
Radial Velocity	1.11
Angular Direction	1.12
Size	1.12
Shape	1.12
Other Target Measurements	1.13
1.4 Radar Frequencies	1.13
HF (3 to 30 MHz)	1.15
VHF (30 to 300 MHz)	1.15
UHF (300 to 1000 MHz)	1.16
L Band (1.0 to 2.0 GHz)	1.16
S Band (2.0 to 4.0 GHz)	1.16

	C Band (4.0 to 8.0 GHz)	1.17
	X Band (8.0 to 12.5 GHz)	1.17
	K _u , K, and K _a Bands (12.5 to 40.0 GHz)	1.17
	Millimeter Wavelengths (above 40 GHz)	1.17
	Laser Frequencies	1.18
1.5	Radar Nomenclature	1.18
2.	Prediction of Radar Range	2.1
2.1	Introduction	2.1
	Definitions	2.1
	Conventions	2.2
	Range Prediction Philosophy	2.2
	Historical Notes	2.3
2.2	Range Equations	2.4
	Radar Transmission Equation	2.4
	Maximum-Range Equation	2.5
	Pulse Radar Equation	2.6
	Detectability Factor	2.6
	Probabilistic Notation	2.8
	Automatic Detection	2.8
	Bistatic Radar Equation	2.9
	Equations in Practical Units	2.9
2.3	Definition and Evaluation of Range Factors	2.10
	Transmitter Power and Pulse Length	2.10
	Antenna Gain, Efficiency, and Loss Factor	2.11
	Antenna Bandwidth	2.12
	Target Cross Section	2.12
	Wavelength (Frequency)	2.13
	Bandwidth and Matching Factors	2.14

2.4	Minimum Detectable Signal-to-Noise Ratio	2.16
	Integration of Signals	2.17
	Number of Pulses Integrated	2.17
	Evaluation of Probabilities	2.18
	Detector Laws	2.23
	Curves for Visual Detection	2.24
	Other Detection Methods	2.25
	Predetection Integration	2.25
2.5	System Noise Temperature	2.26
	Available Power, Gain, and Loss	2.26
	Noise Temperature	2.27
	The Referral Concept	2.27
	Antenna Noise Temperature	2.28
	Transmission-Line Noise Temperature	2.30
	Receiver Noise Temperature	2.31
2.6	Pattern Propagation Factor	2.31
	General Discussion	2.32
	Mathematical Definition	2.35
	Pattern Factor	2.35
	Reflection Coefficient	2.36
	Total Phase Difference	2.37
	Reflection from a Rough Spherical Surface	2.38
	Specular-Reflection Roughness Factor	2.39
	Spherical-Earth Reflection Geometry	2.41
	Divergence Factor	2.42
	Spherical-Earth Pattern Propagation Factor	2.42
	The Intermediate Region	2.43
	Elevation-Angle Interference-Region	
	Calculation	2.43
	Refraction and Coverage Diagrams	2.44

2.7	Loss Factors	2.46
	Antenna Pattern Loss	2.46
	Tropospheric-Absorption Loss	2.47
	Lens-Effect Loss	2.52
	Other Tropospheric Losses	2.54
	Procedure for Range-Dependent Losses	2.54
	Collapsing Loss	2.54
	Signal-Processing Losses	2.55
	Miscellaneous Losses	2.56
2.8	Jamming and Clutter	2.56
	Jamming	2.56
	Clutter	2.57
	Targets in Clutter	2.57
2.9	Cumulative Probability of Detection	2.60
2.10	Accuracy of Radar Range Prediction	2.60
2.11	A Systematic Procedure for Range Prediction	2.61
2.12	Computer Solution of the Range Equation	2.62
3.	Receivers	3.1
3.1	The Configuration of a Radar Receiver	3.1
3.2	Noise and Dynamic-Range Considerations	3.3
	Definitions	3.4
	Evaluation	3.5
3.3	Bandwidth Considerations	3.5
	Definition	3.5
	Important Characteristics	3.5
3.4	Receiver Front End	3.7
	Configuration	3.7
	Effect of Characteristics on Performance	3.7
	Spurious Distortion of Radiated Spectrum	3.7

	Spurious Responses of Mixers	3.8
	Characteristics of Amplifiers and Mixers	3.11
3.5	Local Oscillators	3.11
	Functions of the Local Oscillator	3.11
	Stalo Instability	3.12
	Coho and Timing Instability	3.16
	Total Radar Instability	3.16
3.6	Gain-Controlled Amplifiers	3.17
	Sensitivity Time Control (STC)	3.17
	Clutter Map Automatic Gain Control	3.18
	Automatic Noise-Level Control	3.19
3.7	Filtering	3.19
	Filtering of the Entire Radar System	3.19
	Definitions	3.20
	Approximations to Matched Filters	3.21
	Filtering Problems Associated with Mixer Spurious Responses	3.22
3.8	Logarithmic Devices	3.25
	Characteristics	3.25
	Analog Logarithmic Devices	3.27
	Digital Logarithm	3.28
	Digital Log Power Combiner	3.29
3.9	IF Limiters	3.30
	Applications	3.30
	Characteristics	3.30
3.10	Phase Detectors and Synchronous Detectors	3.32
	Definitions and Characteristics	3.32
	Applications	3.33
	Examples of Phase Detectors	3.36
	Analog-to-Digital Phase Detector	3.37

	Digital Phase Detector	3.38
3.11	Analog-to-Digital Converter	3.38
	Applications	3.38
	Formats	3.39
	Synchronization	3.39
	Performance Characteristics	3.40
	Multiplexing	3.41
3.12	I/Q Distortion Effects and Compensation	
	Methods	3.41
	Gain or Phase Unbalance	3.41
	Time Delay and Pulse Shape Unbalance	3.43
	Nonlinearity in I and Q Channels	3.45
	DC Offset	3.46
3.13	CFAR Detection Processes	3.46
	Application	3.46
	Amplitude-Discrimination CFAR (Cell-Averaging CFAR)	3.47
	Phase-Discrimination CFAR (CPACS)	3.49
	Effect on Range Resolution and Azimuth Accuracy	3.50
	Clutter Map CFAR	3.53
3.14	Diplex Operation	3.54
	Benefits	3.54
	Recommended Implementation	3.54
4.	Transmitters	4.1
4.1	Introduction	4.1
	The Transmitter as Part of a Pulsed Radar System	4.1
	Why So Much Power?	4.2
	Why Pulsed?	4.3

4.2	Magnetron Transmitters	4.5
	Limitations	4.5
	Magnetron Features	4.6
	Common Problems	4.7
4.3	Amplifier Chain Transmitters	4.9
	Oscillator versus Amplifier	4.9
	Amplifier Chains: Special Considerations	4.10
4.4	RF Amplifier Tubes	4.12
	Crossed-Field Amplifiers (CFAs)	4.12
	Klystrons	4.14
	Traveling-Wave Tubes (TWTs)	4.15
	RF Tube Selection	4.17
	RF Tube Power Capabilities	4.21
4.5	Combining and Arraying	4.22
	Hybrid Combining (or Magic T)	4.22
	Phased Arrays	4.23
4.6	Transmitter Stability Requirements	4.25
	Pulsed MTI Systems	4.25
	Pulse Compression Systems	4.27
	Stability Improvement by Feedback or Feedforward	4.30
4.7	Transmitter Spectrum Control	4.31
	Reduction of Spurious Outputs	4.31
	Reduction of Spectrum Amplitude Exceeding ($\sin x$)/ x	4.31
	Improvement over ($\sin x$)/ x by Means of Shaped Pulses	4.31
4.8	Pulse Modulators	4.32
	Line-Type Modulators	4.33
	Active-Switch Modulators	4.35

	Grid Pulsers	4.39
4.9	High-Voltage Crowbars, Regulators, and Power Supplies	4.39
	Crowbars	4.40
	Regulators	4.41
	High-Voltage Power Supplies	4.41
5.	Solid-State Transmitters	5.1
5.1	Introduction	5.1
5.2	Solid-State Microwave Power Generation	5.4
	Microwave Bipolar Power Transistors	5.5
	Microwave Field-Effect Transistors (FETs)	5.9
	Millimeter-Wave Solid-State Power Sources	5.11
5.3	Solid-State Microwave Design	5.12
	High-Power Amplifier Design	5.13
	Phased Array Transceiver Module Design	5.16
	Microwave Monolithic Integrated Circuits	5.16
	Transceiver Module Performance Characteristics	5.18
5.4	Transmitter System Design	5.21
	Performance Sensitivities	5.21
	Power Combining	5.23
	Solid-State Transmitter Design Examples	5.23
6.	Reflector Antennas	6.1
6.1	Introduction	6.1
	Role of the Antenna	6.1
	Beam Scanning and Target Tracking	6.1
	Height Finding	6.2
	Classification of Antennas	6.2

6.2	Basic Principles and Parameters	6.2
	Reciprocity	6.2
	Gain, Directivity, and Effective Aperture	6.3
	Radiation Patterns	6.5
6.3	Types of Antennas	6.10
	Paraboloidal Reflector Antennas	6.12
	Parabolic-Cylinder Antenna	6.15
	Shaped Reflectors	6.17
	Multiple Beams and Extended Feeds	6.19
	Monopulse Feeds	6.21
	Multiple-Reflector Antennas	6.23
	Special-Purpose Reflectors	6.26
6.4	Feeds	6.26
6.5	Reflector Antenna Analysis	6.27
6.6	Shaped-Beam Antennas	6.30
	Gain Estimation	6.31
	Shaped-Beam Antenna Design	6.32
	Antenna Size	6.33
	Accuracy	6.34
6.7	Design Considerations	6.34
	Feed Blockage	6.34
	Feed Spillover and Diffraction	6.37
	Surface Leakage	6.40
6.8	Mechanical Considerations	6.40
6.9	Radomes	6.44
	Types of Radomes and General Considerations	6.44
	Environmental Effects	6.45
	Airborne and Missile Radomes	6.46
	Ground and Shipboard Radomes	6.47

	Other Radome Effects	6.48
6.10	Antenna Testing	6.52
	Pattern Test Ranges	6.52
	Elevated Ranges	6.53
	Ground Ranges	6.55
	Compact Ranges	6.56
	Near-Field Ranges	6.57
	Miscellaneous Tests	6.59
7.	Phased Array Radar Antennas	7.1
7.1	Introduction	7.1
	Phased Array Radars	7.1
	Scanning of Arrays	7.7
7.2	Array Theory	7.10
7.3	Planar Arrays and Beam Steering	7.17
	Planar Arrays	7.17
	Element-Phasing Calculations	7.21
7.4	Aperture Matching and Mutual Coupling	7.22
	Significance of Aperture Matching	7.22
	Effects of Mutual Coupling	7.23
	Element Pattern	7.25
	Thinned Arrays	7.26
	Impedance Variation of Free Space	7.27
	Element Impedance	7.27
	Analytical Techniques	7.29
	Nonisolating Feeds	7.30
	Mutual Coupling and Surface Waves	7.31
	Array Simulators	7.32
	Compensation for Scanned Impedance Variation	7.35

	Small Arrays	7.35
7.5	Low-Sidelobe Phased Arrays	7.37
	Illumination Functions	7.37
	Effect of Errors	7.38
	Random Errors	7.39
7.6	Quantization Effects	7.43
	Phase Quantization	7.43
	Periodic Errors	7.45
7.7	Bandwidth of Phased Arrays	7.49
	Aperture Effects	7.49
	Feed Effect	7.51
	Broad Instantaneous Bandwidth	7.53
	Time-Delay Networks	7.56
7.8	Feed Networks (Beamformers)	7.58
7.9	Phase Shifters	7.63
	Diode Phasers	7.63
	Ferrite Phasers	7.64
7.10	Solid-State Modules	7.67
7.11	Phased Array Systems	7.69
8.	Automatic Detection, Tracking, and Sensor Integration	8.1
8.1	Introduction	8.1
8.2	Automatic Detection	8.1
	Optimal Detector	8.2
	Practical Detectors	8.3
	False-Alarm Control	8.12
	Target Resolution	8.21
	Detection Summary	8.23

8.3	Automatic Tracking	8.23
	Track-While-Scan Systems	8.24
	Maximum-Likelihood Approaches	8.38
8.4	Multisensor Integration	8.40
	Colocated Radar Integration	8.42
	Multisite Radar Integration	8.43
	Unlike-Sensor Integration	8.44
9.	Electronic Counter-Countermeasures	9.1
9.1	Introduction	9.1
9.2	Terminology	9.2
9.3	Electronic Warfare Support Measures	9.2
9.4	Electronic Countermeasures	9.4
9.5	Objectives and Taxonomy of ECCM Techniques	9.7
9.6	Antenna-Related ECCM	9.7
	Sidelobe-Blanking (SLB) System	9.9
	Sidelobe Canceler (SLC) System	9.11
	Adaptive Arrays	9.14
9.7	Transmitter-Related ECCM	9.16
9.8	Receiver-Related ECCM	9.18
9.9	Signal-Processing-Related ECCM	9.19
9.10	Operational-Deployment Techniques	9.21
9.11	Application of ECCM Techniques	9.22
	Surveillance Radars	9.23
	Tracking Radars	9.25
9.12	ECCM and ECM Efficacy	9.28
	The Radar Equation in Jamming and Chaff Conditions	9.29

10. Pulse Compression Radar	10.1
10.1 Introduction	10.1
10.2 Factors Affecting Choice of Pulse Compression System	10.3
10.3 Linear FM	10.4
10.4 Nonlinear FM	10.4
10.5 Pulse Compression Devices	10.6
Digital Pulse Compression	10.7
Surface-Wave Pulse Compression	10.10
Other Passive Linear-FM Devices	10.12
Voltage-Controlled Oscillator	10.15
10.6 Phase-Coded Waveforms	10.15
Optimal Binary Sequences	10.17
Maximal-Length Sequences	10.19
Quadratic Residue Sequences	10.21
Complementary Sequences	10.21
Implementation of Biphase-Coded Systems	10.22
Doppler Correction	10.24
Polyphase Codes	10.25
10.7 Time-Frequency-Coded Waveforms	10.26
10.8 Weighting and Equalization	10.27
Paired Echoes and Weighting	10.27
Comparison of Weighting Functions	10.29
Taylor versus Cosine-Squared-Plus-Pedestal Weighting	10.31
Taylor Weighting with Linear FM	10.31
Discrete Time Weighting	10.34
Amplitude and Phase Distortion	10.34
Equalization	10.36

11. Radar Cross Section	11.1
11.1 Introduction	11.1
11.2 The Concept of Echo Power	11.2
Definition of RCS	11.2
Examples of RCS Characteristics	11.4
11.3 RCS Prediction Techniques	11.18
Exact Methods	11.20
Approximate Methods	11.24
11.4 RCS Measurement Techniques	11.34
General Requirements	11.35
Outdoor Test Ranges	11.38
Indoor Test Ranges	11.39
11.5 Echo Reduction	11.43
Shaping	11.44
Radar Absorbers	11.46
11.6 Summary	11.51
12. Ground Echo	12.1
12.1 Introduction	12.1
Relative Importance of Theory and Empiricism	12.3
Available Scattering Information	12.3
12.2 Parameters Affecting Ground Return	12.4
12.3 Theoretical Models and Their Limitations	12.6
Descriptions of a Surface	12.6
Simplified Models	12.7
Physical Optics Models	12.9
Small-Perturbation and Two-Scale Models	12.10
Other Models	12.12

12.4	Fading of Ground Echoes	12.12
	Fading-Rate Computations	12.13
	Effect of Detection	12.16
	Moving Target Surfaces	12.18
12.5	Measurement Techniques for Ground Return	12.18
	CW and FM-CW Systems	12.18
	Range-Measuring Systems	12.21
	CW-Doppler Scatterometers	12.22
	Independent Samples Required for Measurement Accuracy	12.23
	Near-Vertical Problem	12.23
	Ground and Helicopter Scatterometers and Spectrometers	12.24
	Scattering Coefficient from Images	12.28
	Bistatic Measurements	12.28
12.6	General Models for Scattering Coefficient (Clutter Models)	12.28
12.7	Scattering Coefficient Data	12.35
	Effects of Roughness, Moisture Content, and Vegetation Cover	12.35
	Soil Moisture	12.39
	Vegetation	12.41
	Snow	12.42
	Sea Ice	12.44
12.8	Imaging Radar Interpretation	12.45
13.	Sea Clutter	13.1
13.1	Introduction	13.1
13.2	Description of the Sea Surface	13.2
	The Wave Spectrum	13.3
	General Sea Descriptors	13.5

13.3	Empirical Behavior of Sea Clutter	13.6
	Dependence on Wind Speed, Grazing Angle, and Frequency	13.8
	The Spectrum of Sea Clutter	13.21
	Other Effects on Sea Clutter	13.23
13.4	Theories of Sea Clutter	13.27
	Theories Based on Global Boundary-Value Problems	13.29
	The Composite-Surface Hypothesis	13.32
	Scattering by Surface Features	13.33
13.5	Summary and Conclusions	13.35
14.	CW and FM Radar	14.1
14.1	Introduction and Advantages of CW	14.1
14.2	Doppler Effect	14.2
14.3	Unmodulated CW Radar	14.2
	Spectral Spreading	14.2
	Noise in Sources	14.3
	Noise from Clutter	14.3
	Microphonism	14.7
	Scanning and Target Properties	14.7
14.4	Sources	14.8
	Master Oscillator Power Amplifier (MOPA) Chains	14.8
	Active Stabilization	14.8
	Stabilization of Power Oscillators	14.11
14.5	Noise Measurement Technique	14.11
14.6	Receivers	14.15
	RF Amplification	14.15
	Generation of the Local-Oscillator Signal	14.15

IF Amplifier	14.16
Subcarriers	14.16
Amplification	14.18
Doppler Filter Banks	14.18
Doppler Trackers	14.18
Constant False-Alarm Rate (CFAR)	14.19
14.7 Minimization of Feedthrough	14.19
14.8 Miscellaneous CW Radars	14.20
CW Proximity Fuzes	14.20
Police Radars	14.21
14.9 FM Radar	14.21
14.10 Sinusoidal Modulation	14.23
Double Sinusoidal Modulation	14.26
14.11 Triangular and Sawtooth Modulation	14.27
14.12 Noise Modulation	14.28
14.13 Coded Modulations	14.29
14.14 Dual Modulation	14.30
14.15 Leakage	14.30
14.16 Performance of FM-CW Systems	14.31
14.17 Short-Range Systems and Microwave Proximity Fuzes	14.31
14.18 Altimeters	14.34
14.19 Doppler Navigators	14.37
14.20 Personnel Detection Radar and Miscellaneous FM-CW Systems	14.39
14.21 Tailoring the Range Response of FM-CW Systems	14.41

15. MTI Radar	15.1
15.1 Introduction to MTI Radar	15.1
Moving-Target Indicator (MTI) Block Diagram	15.3
Moving-Target Detector (MTD) Block Diagram	15.5
15.2 Clutter Filter Response to Moving Targets	15.7
15.3 Clutter Characteristics	15.8
Spectral Characteristics	15.8
Amplitude Characteristics	15.10
15.4 Definitions	15.11
Improvement Factors (I)	15.11
Signal-to-Clutter Ratio Improvement (I_{SCR})	15.11
Subclutter Visibility (SCV)	15.13
Interclutter Visibility (ICV)	15.13
Filter Mismatch Loss	15.14
Clutter Visibility Factor (V_{OC})	15.14
15.5 Improvement Factor Calculations	15.14
15.6 Optimum Design of Clutter Filters	15.16
15.7 MTI Clutter Filter Design	15.23
15.8 Clutter Filter Bank Design	15.29
Empirical Filter Design	15.29
Chebyshev Filter Bank	15.31
Fast Fourier Transform Filter Bank	15.34
15.9 Staggered PRF	15.34
Stagger Design Procedures	15.34
Feedback and Pulse-to-Pulse Staggering	15.37
Improvement Factor Limitation Caused by Staggering	15.39
Time-Varying Weights	15.40

	Depth of First Null in Velocity Response	15.40
15.10	Improvement Factor Restriction Caused by Limiting	15.41
15.11	Radar System Stability and A/D Quantization Requirements	15.45
	System Instabilities	15.45
	Effect of Quantization Noise on Improvement Factor	15.53
	Pulse Compression Considerations	15.55
15.12	Analog-to-Digital Conversion Considerations	15.57
	Dynamic Range	15.58
	I and Q Balance Requirements	15.59
	Timing Jitter	15.60
	Linearity	15.60
	Accuracy	15.60
15.13	Adaptive MTI Implementation	15.61
15.14	Clutter Map Implementation	15.65
15.15	Considerations Applicable to MTI Radar Systems	15.69
16.	Airborne MTI	16.1
16.1	Systems Using Airborne MTI Techniques	16.1
16.2	Coverage Considerations	16.2
16.3	Platform Motion and Altitude Effects on MTI Performance	16.2
	Effect of Slant Range on Doppler Effect	16.4
	TACCAR	16.5
	Platform-Motion Effect	16.7
16.4	Platform-Motion Compensation Abeam	16.8
	Physically Displaced Phase-Center Antenna	16.8

	Electronically Displaced Phase-Center Antenna	16.10
	Power in the Antenna Sidelobes	16.13
16.5	Scanning-Motion Compensation	16.14
	Compensation-Pattern Selection	16.16
16.6	Simultaneous Platform Motion and Scan Compensation	16.17
16.7	Platform-Motion Compensation, Forward Direction	16.20
16.8	Space-Time Adaptive Motion Compensation	16.23
	Performance Capability of Space-Time Adaptive Arrays	16.26
16.9	Limitation of Improvement Factor Due to Pulse Envelope Shift	16.28
16.10	Effect of Multiple Spectra	16.29
16.11	Detection of Ground Moving Targets	16.29
17.	Pulse Doppler Radar	17.1
17.1	Characteristics and Applications	17.1
	Nomenclature	17.1
	Applications	17.1
	PRFs	17.1
	Pulse Doppler Spectrum	17.2
	Ambiguities and PRF Selection	17.5
	Basic Configuration	17.7
17.2	Pulse Doppler Clutter	17.9
	General	17.9
	Ground Clutter in a Stationary Radar	17.9
	Ground Clutter in a Moving Radar	17.9
	Clutter Return: General Equations	17.10
	Sidelobe Clutter	17.11

	Sidelobe Discretas	17.11
	Main-Beam Clutter	17.16
	Main-Beam Clutter Filtering	17.16
	Altitude-Line Clutter Filtering	17.18
17.3	Time Gating	17.19
	Transmitted-Pulse Suppression	17.19
	Range Gating	17.19
17.4	Range-Ambiguity Resolution	17.19
	High-PRF Ranging	17.20
	Medium-PRF Ranging	17.25
17.5	Target Tracking	17.25
	Single-Target Tracking	17.25
	Multiple-Target Tracking	17.26
17.6	Dynamic-Range and Stability Requirements	17.26
	Dynamic Range	17.26
	Stability Requirements	17.28
	Types of Spurious Modulation	17.29
	Sinusoidal Modulations	17.29
	Pulse-to-Pulse Random Modulation	17.33
17.7	Range Performance	17.33
	Range Equation	17.33
	System Losses	17.33
	Probability of False Alarm	17.35
	Probability of Detection	17.36
18.	Tracking Radar	18.1
18.1	Introduction	18.1
18.2	Scanning and Lobing	18.3
18.3	Monopulse (Simultaneous Lobing)	18.8
	Amplitude-Comparison Monopulse	18.9

	Phase-Comparison Monopulse	18.17
	Monopulse Tracking with Phased Arrays	18.19
	One- and Two-Channel Monopulse	18.19
	Conopulse	18.21
18.4	Servosystems for Tracking Radar	18.22
18.5	Target Acquisition and Range Tracking	18.26
	Acquisition	18.26
	Range Tracking	18.27
	<i>n</i> th-Time-Around Tracking	18.30
18.6	Special Monopulse Techniques	18.30
	High-Range-Resolution Monopulse	18.30
	Dual-Band Monopulse	18.31
	Mirror Antenna (Inverse Cassegrain)	18.32
	On-Axis Tracking	18.33
18.7	Sources of Error	18.33
18.8	Target-Caused Errors (Target Noise)	18.34
	Amplitude Noise	18.34
	Angle Noise (Glint)	18.37
	Range Noise (Range Glint)	18.43
	Doppler Scintillation	18.45
18.9	Other External Causes of Error	18.46
	Multipath	18.46
	Crosstalk Caused by Cross-Polarized Energy	18.48
	Troposphere Propagation	18.49
18.10	Internal Sources of Error	18.50
	Receiver Thermal Noise	18.50
	Other Internal Sources of Error	18.52
18.11	Summary of Sources of Error	18.53
	Angle Measurement Errors	18.53

	Range Measurement Errors	18.54
18.12	Error Reduction Techniques	18.54
	Multipath-Error Reduction	18.54
	Target Angle and Range Scintillation (Glint) Reduction	18.57
	Reduction of Internally Caused Errors	18.57
19.	Radar Guidance of Missiles	19.1
19.1	Introduction	19.1
19.2	Overview of Semiactive CW Systems	19.3
	Doppler Frequency Relationships	19.3
	Clutter and Feedthrough Considerations	19.6
	Guidance Fundamentals	19.7
	Target Illumination	19.9
19.3	System Evolution	19.9
	Basic Semiactive Seeker	19.10
	Unambiguous (Offset Video) Receiver	19.10
	Inverse Receiver	19.12
	Angle Tracking: Conical Scan to Monopulse	19.14
	Pulse Doppler (PD) Operation	19.15
	Active Seekers	19.15
	Passive Seekers	19.17
	Other System Considerations	19.20
19.4	System Functional Operation	19.21
	Reference-Channel Operation	19.21
	Target Signal Detection	19.23
	Target Signal Tracking	19.26
	Performance Limitations	19.29
19.5	Subsystems and Integration	19.31
	Radome	19.32

	Antenna	19.33
	Receiver	19.35
	Low-Noise Frequency Reference	19.37
	Signal Processing	19.37
	Transmitter	19.38
	Power	19.40
	Integration	19.40
20.	Height Finding and 3D Radar	20.1
20.1	Height Finding Radars and Techniques	20.1
	Early Radar Techniques for Height Finding	20.1
	Height Finding Techniques in 3D Radars	20.6
20.2	Derivation of Height from Radar Measurements	20.14
	Flat-Earth Approximation	20.14
	Spherical Earth: Parabolic Approximation	20.14
	Spherical Earth: Exact Geometry	20.14
	Corrections for Atmospheric Refraction	20.15
	Practical Corrections	20.19
20.3	Height Accuracy Performance Limitations	20.19
	Fundamental Accuracy of Sequential Lobing	20.20
	Fundamental Accuracy of Simultaneous Lobing	20.25
	Elevation Error Due to Surface Reflections	20.33
	Low-Angle Squinted-Beam Height Finding	20.35
21.	Synthetic Aperture Radar	21.1
21.1	Basic Principles and Early History	21.1
21.2	Factors Affecting Resolution of a Radar System	21.4
	Conventional Technique	21.4

	The Unfocused Synthetic Aperture	21.5
	The Focused Case	21.6
21.3	Radar System Preliminaries	21.7
21.4	Signal-Processing Theory	21.8
	Detailed Resolution Analysis	21.8
	Signal-to-Noise-Ratio Considerations	21.15
	Effect of Phase Errors	21.17
	Signal Processing	21.17
21.5	Additional System Considerations	21.18
	Antenna	21.18
	Receiver-Transmitter	21.19
	Storage and Recording	21.19
	Motion Compensation	21.20
	Squint Mode	21.20
	Spotlight Mode	21.21
	Effects of Motion Errors	21.21
	Multiple-Beam Radars	21.21
	ISAR	21.21
	Three-Dimensional Spectrum	21.21
22.	Space-Based Radar Systems and Technology	22.1
22.1	Introduction	22.1
22.2	SBR Systems Considerations	22.1
	Types of SBR	22.1
	Considerations	22.5
22.3	SBR System Descriptions	22.14
	STS Rendezvous Radar	22.14
	Seasat-A Synthetic Aperture Radar	22.15
	Shuttle Imaging Radar	22.15

	GEOS-C SBR System Characteristics	22.15
	U.S.S.R. Cosmos 1500 Side-Looking Radar	22.17
22.4	Technology	22.17
	Antennas	22.18
	Transmit/Receive Modules	22.23
	On-Board Processors	22.24
	Prime Power	22.24
22.5	Critical Issues	22.26
	SBR System Costs	22.26
	Survivability and Vulnerability	22.26
22.6	SBR Future Possibilities	22.26
	Rendezvous Radar Missions	22.26
	Remote-Sensing Missions	22.29
	Global Air Traffic Surveillance	22.30
	Military SBR Systems	22.31
23.	Meteorological Radar	23.1
23.1	Introduction	23.1
23.2	The Radar Range Equation for Meteorological Targets	23.2
23.3	Design Considerations	23.5
	Attenuation Effects	23.5
	Range and Velocity Ambiguities	23.10
	Ground Clutter Effects	23.11
	Typical Weather Radar Designs	23.12
23.4	Signal Processing	23.13
	Measurement Accuracy	23.15
	Processor Implementations	23.17
23.5	Operational Applications	23.17
	Precipitation Measurement	23.18

	Severe Storm Warning	23.19
23.6	Research Applications	23.23
	Multiple-Parameter, Radar	23.23
	Multiple Radars	23.24
	Rapid Scanning	23.25
	Airborne and Space-Borne Radars	23.26
	Clear-Air Radars	23.27
	Synthetic Aperture Radar and Pulse Compression	23.28
24.	HF Over-the-Horizon Radar	24.1
24.1	Introduction	24.1
24.2	Radar Equation	24.3
24.3	Transmitters	24.4
24.4	Antennas	24.5
24.5	Clutter: The Echo from the Earth	24.6
24.6	Radar Cross Section	24.10
24.7	Noise and Interference	24.12
24.8	Spectrum Use	24.14
24.9	Sky-Wave Transmission Medium	24.15
24.10	Sky-Wave Radar Performance	24.22
24.11	Receiver-Processor	24.36
24.12	Ground-Wave Radar Performance	24.38
25.	Bistatic Radar	25.1
25.1	Concept and Definitions	25.1
25.2	History	25.2
25.3	Coordinate System	25.5
25.4	Range Relationships	25.6
	Range Equation	25.6
	Ovals of Cassini	25.6

	Operating Regions	25.7
	Isorange Contours	25.8
25.5	Area Relationships	25.9
	Location	25.9
	Coverage	25.10
	Clutter Cell Area	25.12
25.6	Doppler Relationships	25.13
	Target Doppler	25.13
	Isodoppler Contours	25.14
25.7	Target Cross Section	25.14
	Pseudo-Monostatic RCS Region	25.15
	Bistatic RCS Region	25.17
	Glint Reduction in the Bistatic RCS Region	25.17
	Forward-Scatter RCS Region	25.17
25.8	Clutter	25.18
	In-Plane Land Clutter Scattering Coefficient	25.21
	In-Plane Sea Clutter Scattering Coefficient	25.24
	Out-of-Plane Scattering Coefficient	25.24
25.9	Special Techniques, Problems, and Requirements	25.24
	Pulse Chasing	25.24
	Beam Scan on Scan	25.26
	Sidelobe Clutter	25.27
	Time Synchronization	25.27
	Phase Synchronization and Stability	25.28
	<i>Index</i>	1.1