

Software-Defined Ground Penetrating Radar Using COTS SDRs and GNU Radio Companion

2025 GNU Radio Conference

Gavin Messerly

Collaboration with the 309th SWEG under the Educational Partnership Agreement (EPA) between Weber State University and Hill AFB



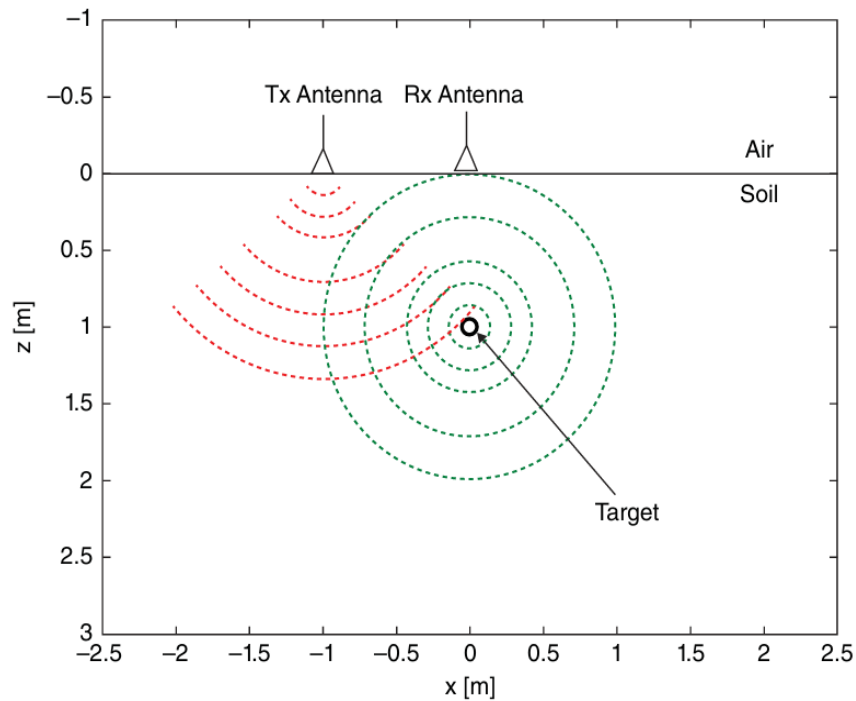
Project Overview

- Collaboration with 309th Software Engineering Group:
 - Landmine detection: Shallow Depth, High Resolution
 - Size: 8 – 30 cm wide
 - Depth: < 30 cm
- Goal:
 - Explore SD-GPR viability for detection of shallowly buried targets
- Evaluation:
 - Characterize performance against known targets and COTS product

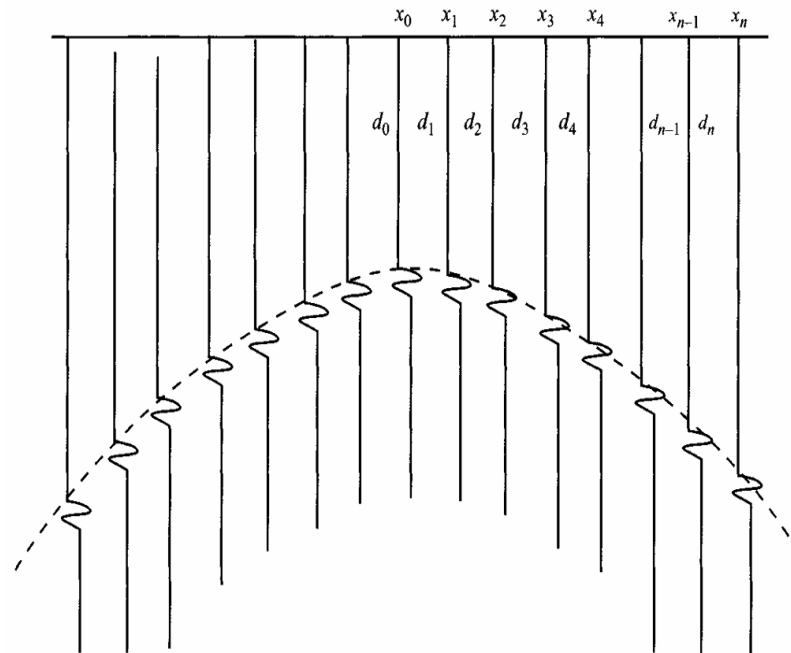


Background

- GPR: a radar to identify subsurface discontinuities



The working principle of a GPR (R. Persico 2014)



B-scan Radargram Construction (D. J. Daniels 2004)



Traditional GPR System (R. Persico 2014)

Motivation

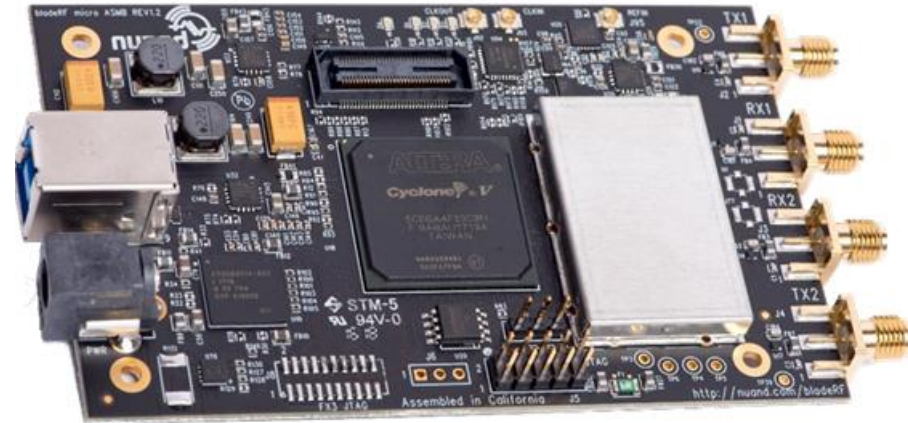
- Interest in drone-based GPR systems
 - Reduces:
 - Labor
 - Time
 - Risk
 - Issues:
 - Expensive
 - Power-Intensive
 - Large and Heavy
- SDRs are a potential solution



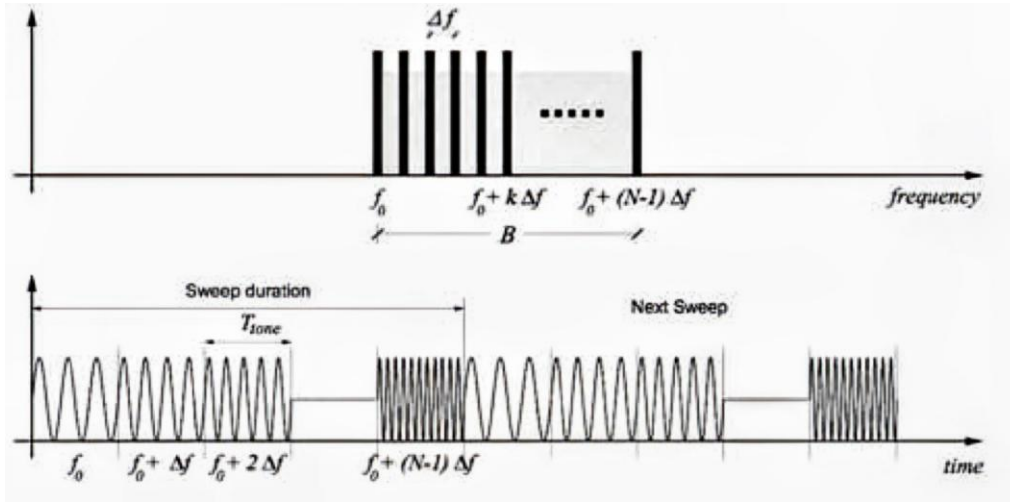
Drone-Based GPR System

Approach

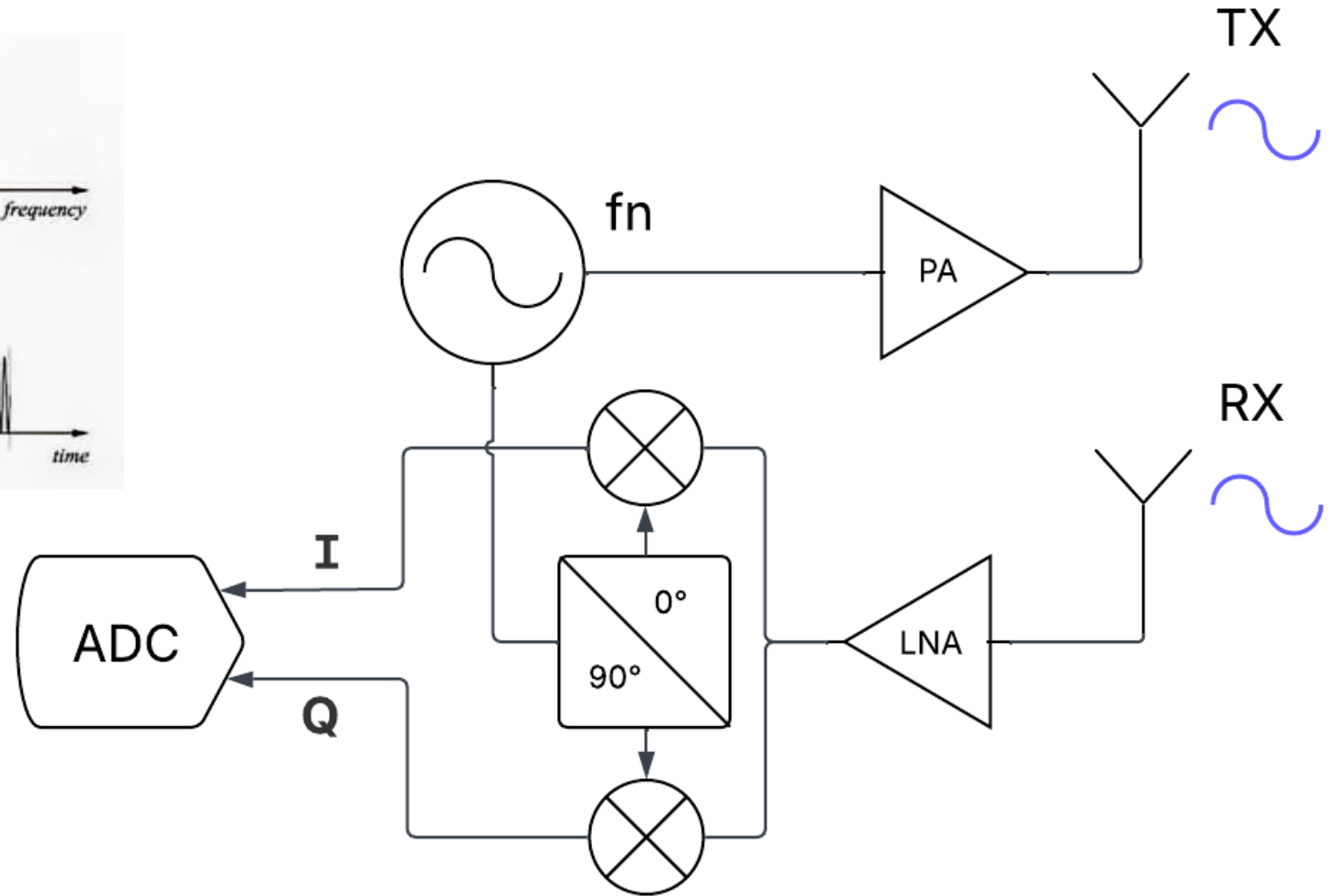
- Stepped Frequency Continuous Wave Radar (SFCW)
 - Low power requirements
 - High SNR
- COTS SDR Platform
 - BladeRF 2.0 Micro xA9
- Open-Source Software
 - GNU Radio Companion
 - Python3



SFCW Theory of Operation



SFCW waveform in frequency and time (C. Gentile 2010)



Radar Specifications

$$\Delta R = \frac{c}{2B} = \frac{c}{2N\Delta f}$$

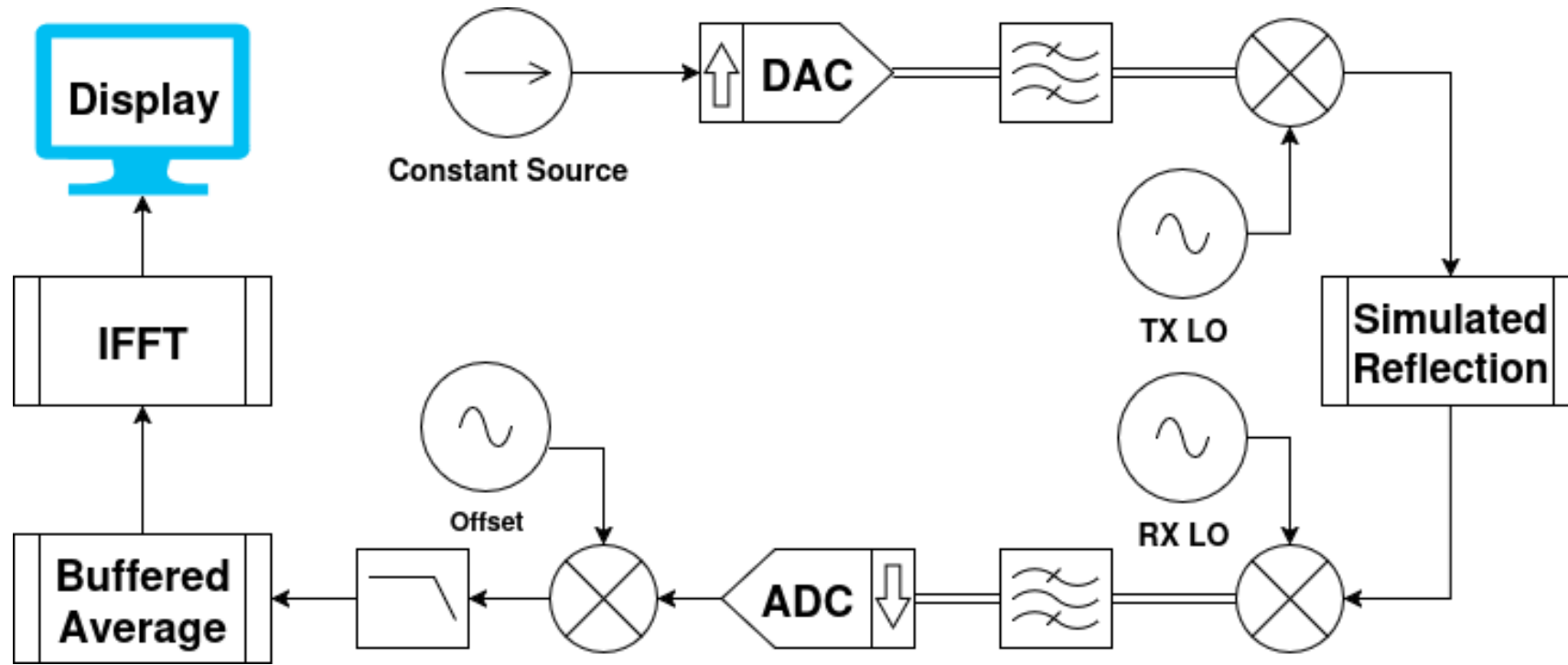
$$R_{max} = \Delta R N = \frac{c}{2\Delta f}$$

Equations for Range Resolution (ΔR) and Maximum Unambiguous Range (R_{max})

- $\Delta R = 6 \text{ cm}$
- $R_{max} = 6 \text{ m}$
- $B = 2.5 \text{ GHz}$ (600 MHz – 3.1 GHz)
- $N = 100$
- $\Delta f = 25 \text{ MHz}$

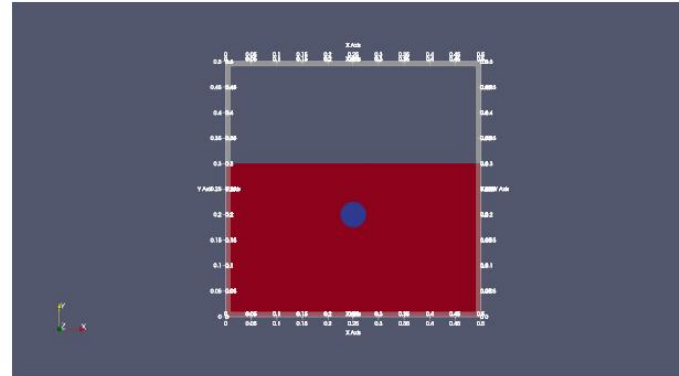


Simulated Architecture

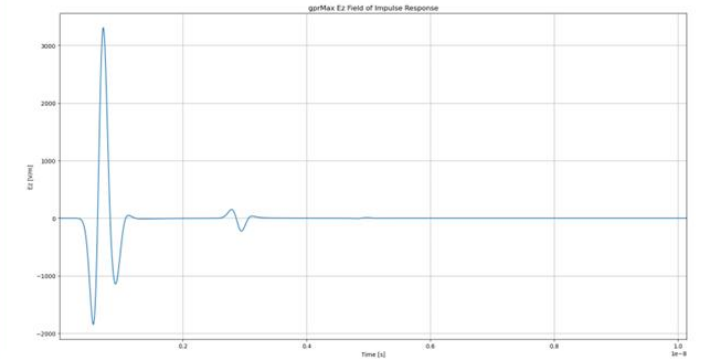


Simulated Reflection

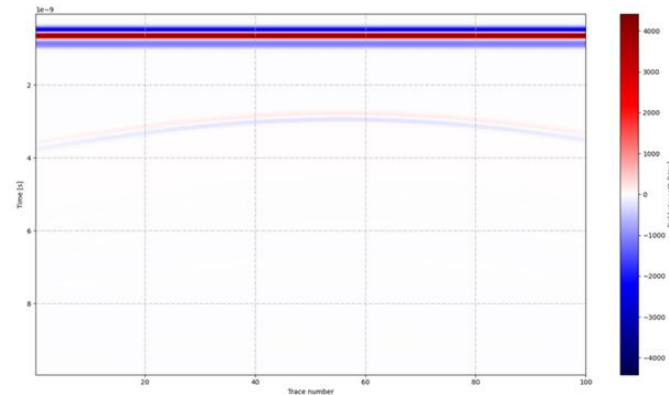
- GPR system can be approximated as LTI
- gprMax generates impulse response and comparison
- Python3 Processing
 - Frequency Synthesis
 - Convolution
 - Range Correlation



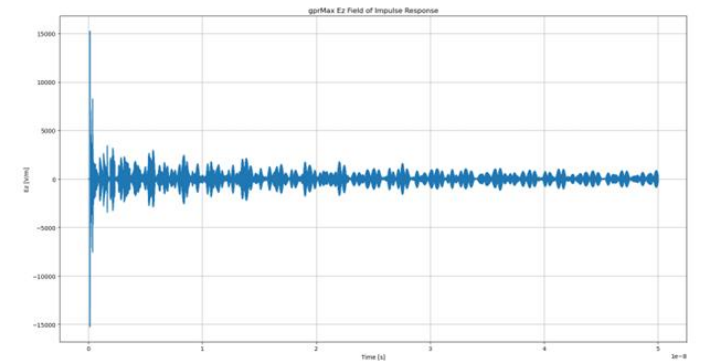
(a) Visualization of GPR Environment



(b) Gaussian Dot Norm A-scan for System

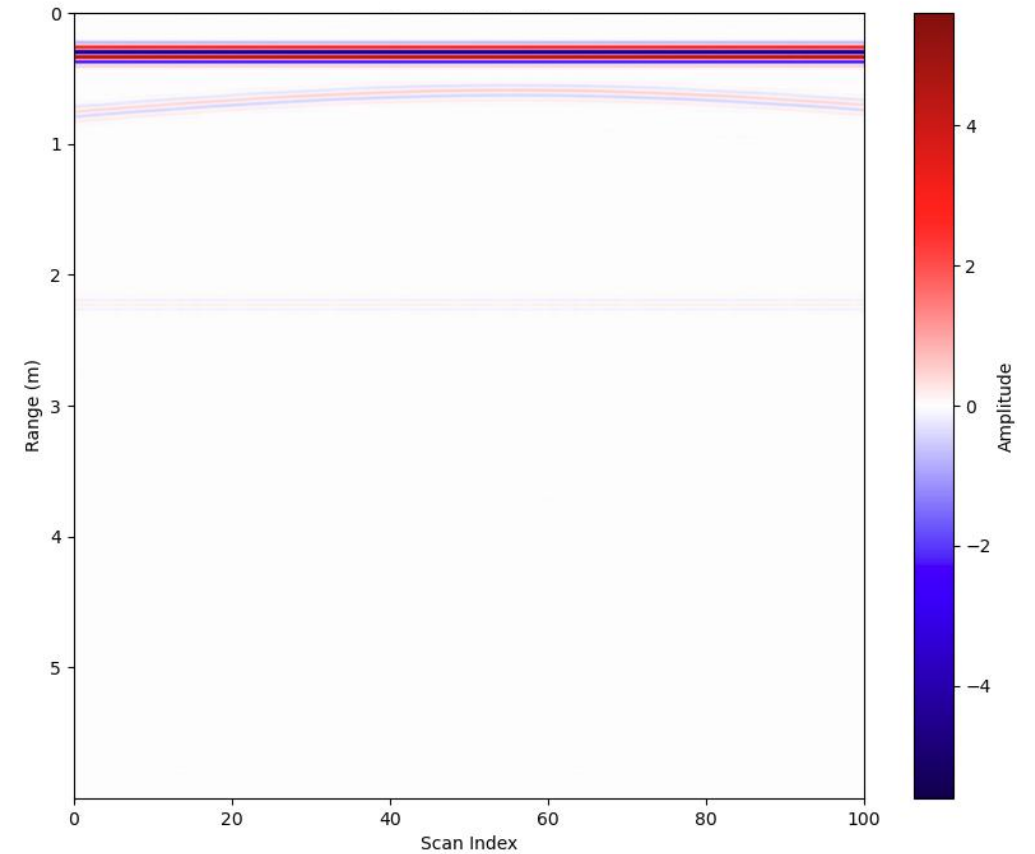
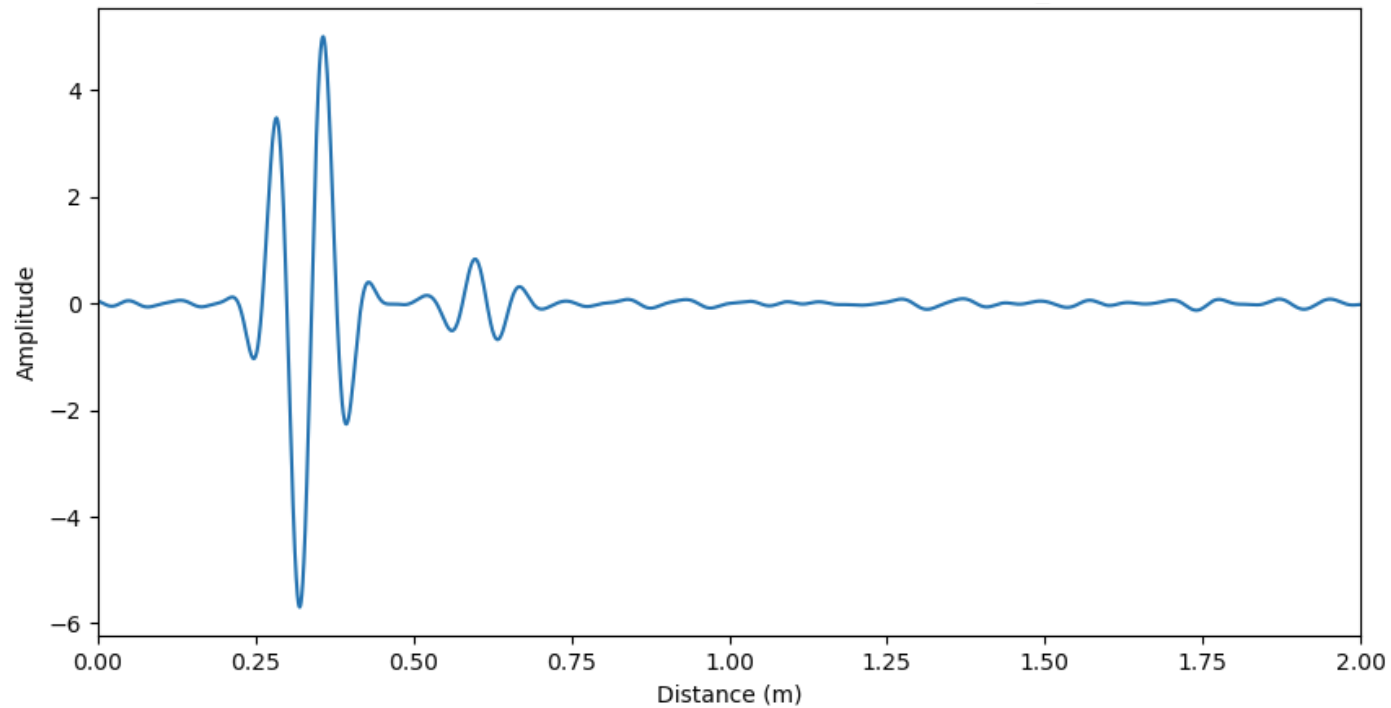


(c) Gaussian Dot Norm B-scan for System



(d) Impulse Response Generated by gprMax

Simulation Results



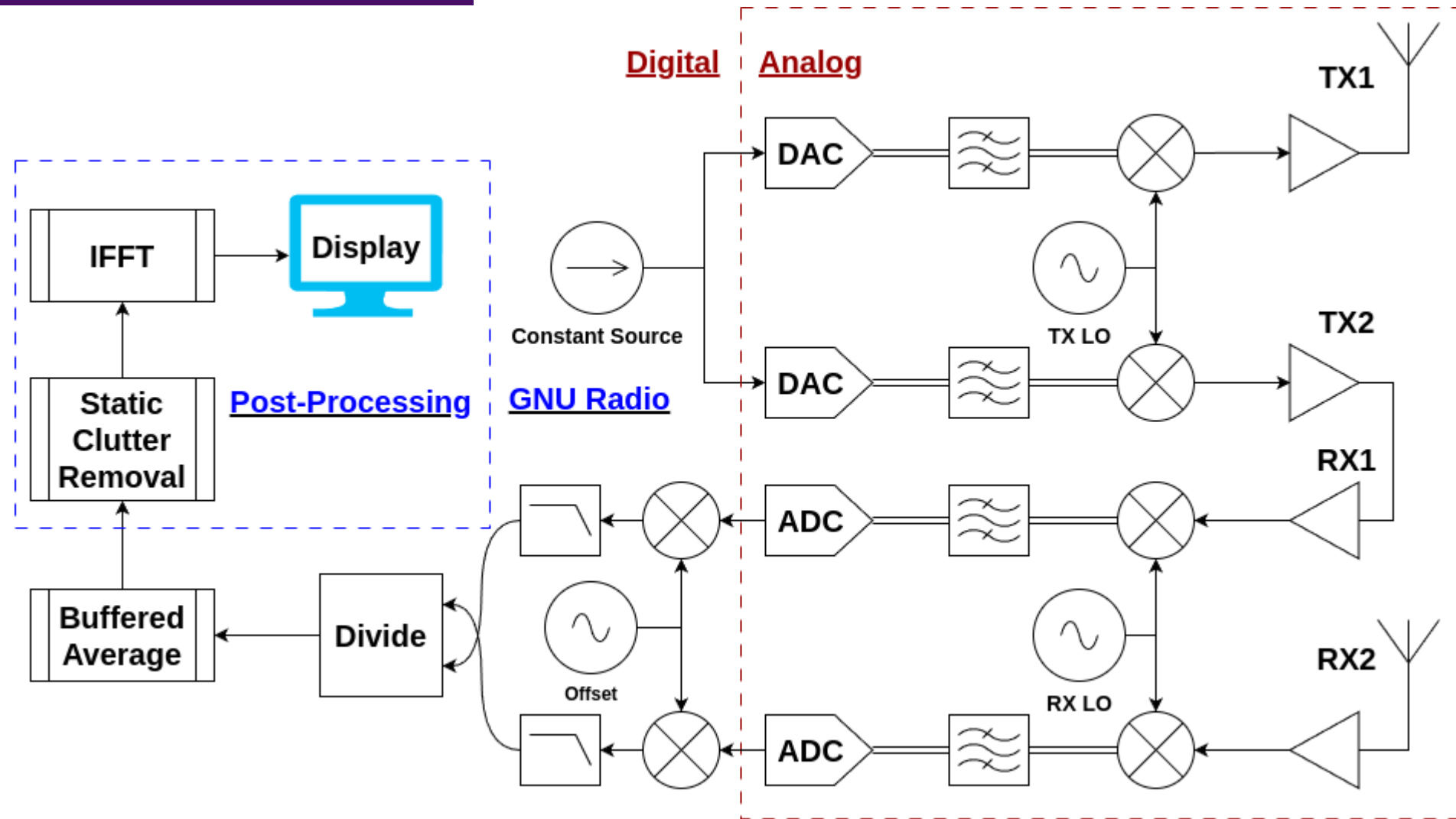
Hardware Overview

- SDR: BladeRF 2.0 Micro
 - 2x2 MIMO transceiver
 - 12-bit ADCs/DACs
 - Tuning range : 47 MHz – 6 GHz
- Antennas: TSA600 Vivaldi antennas
 - High performance, wideband: 600 MHz – 6 GHz
- Shared clock source but separate RX and TX oscillators
 - Precisely Same Frequency
 - Non-Deterministic Phase Difference

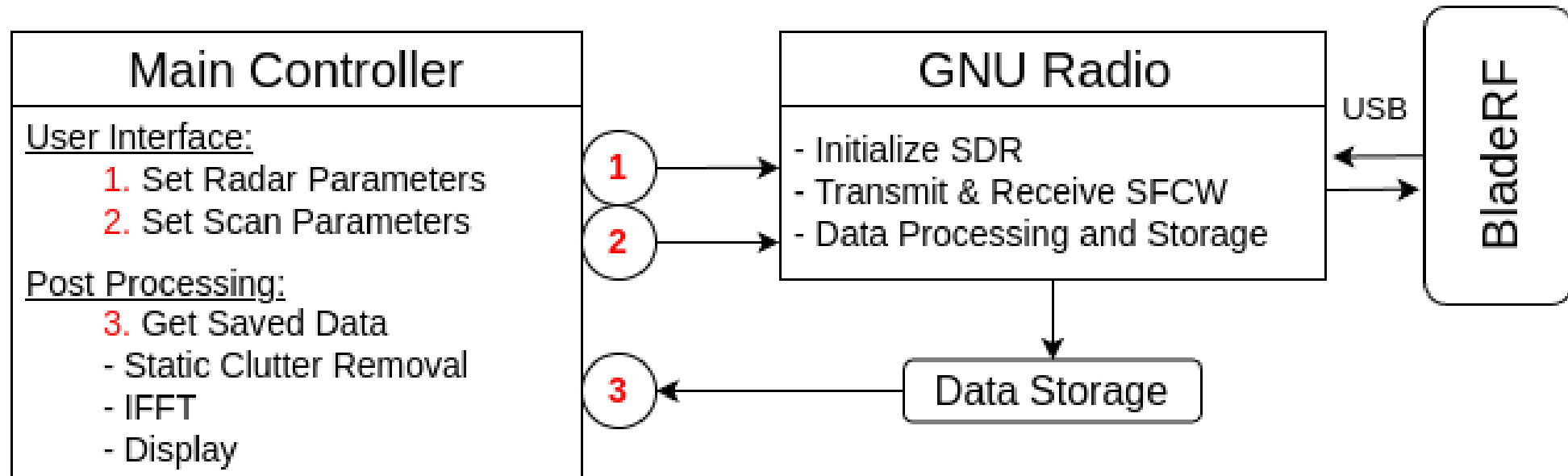


SD-GPR Test Rig

Proposed SD-GPR Architecture

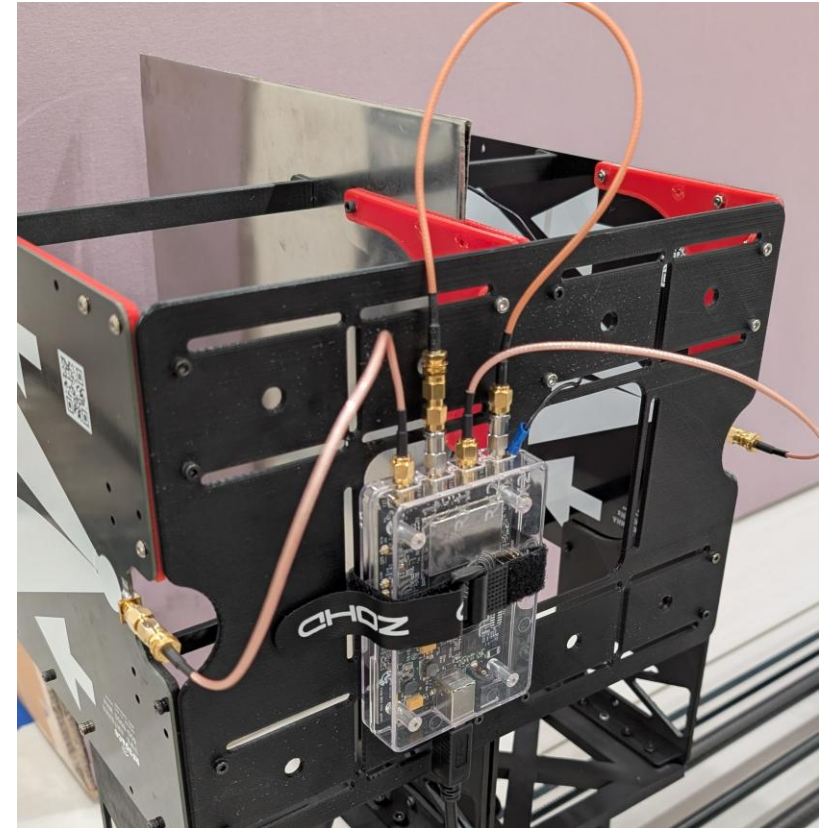


Software Overview



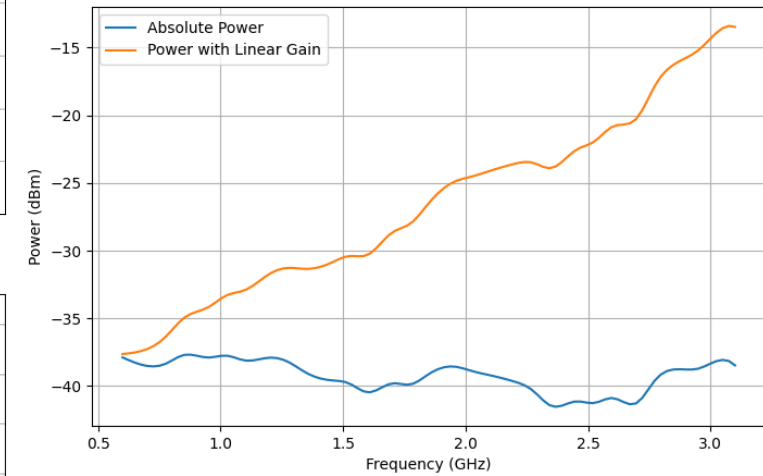
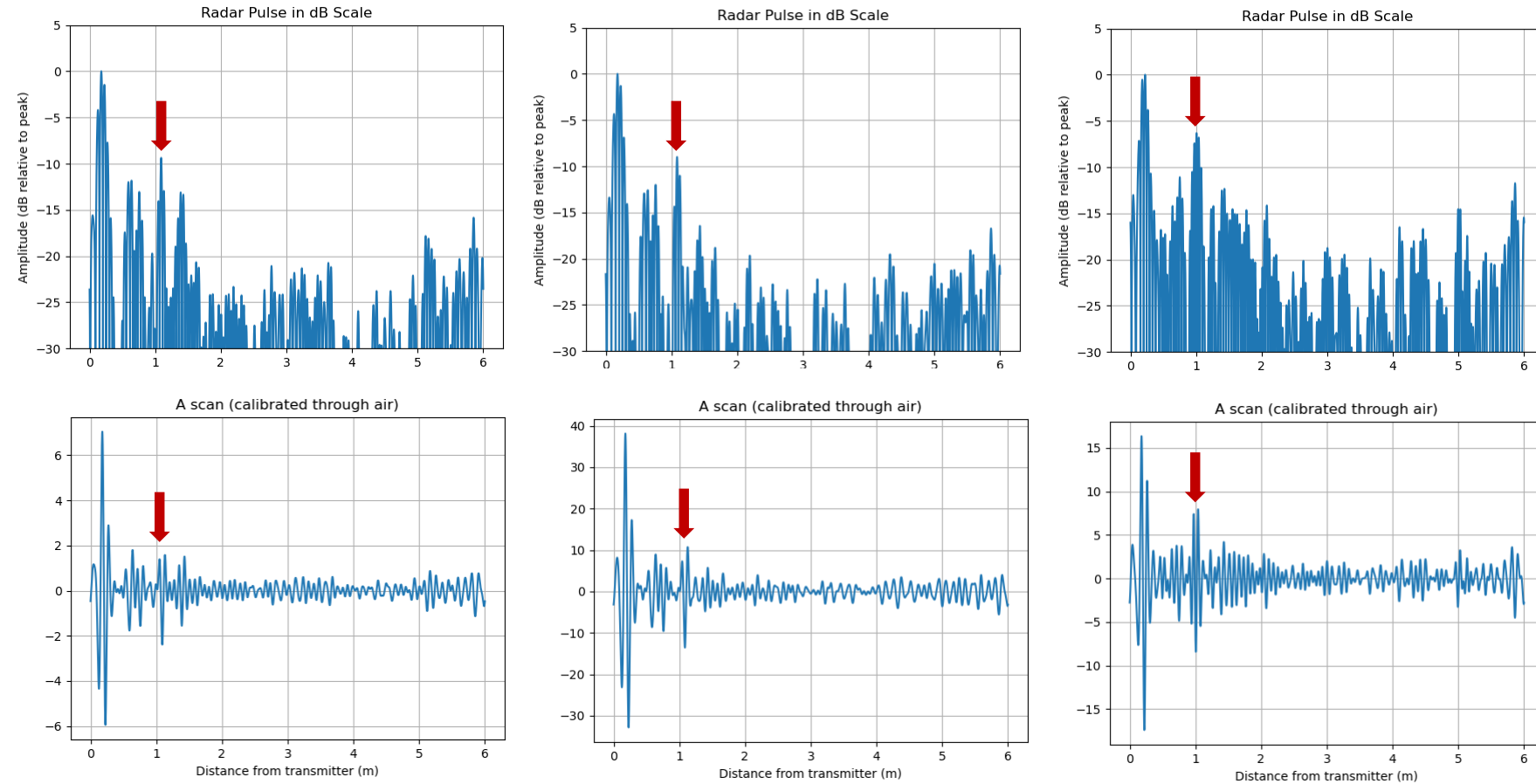
Receiver Calibration

- Two Phase Offsets:
 - Local Oscillator(LO) Phase Difference
 - Signal Propagation Phase Offset
- LO Phase Difference:
 - Reference Line Division
 - Isolates Absolute Change in Mag./Phase
- Signal Propagation Offset
 - Measured
 - Constant Phase Shift Applied



Reference Line Connections

Transmitter Calibration



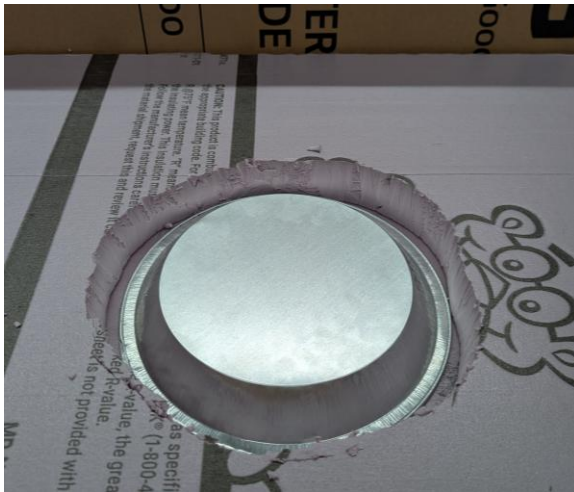
TX Power Frequency Response



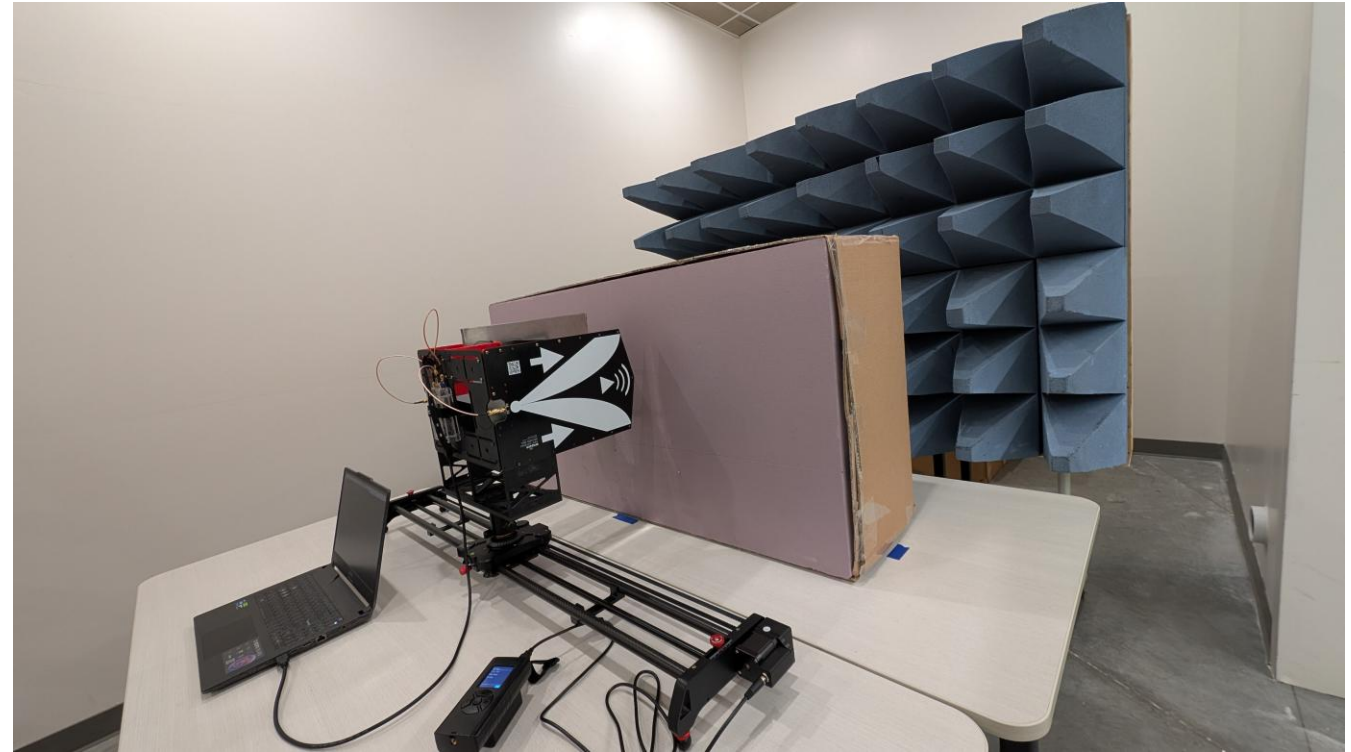
Experiment Setup



COTS GPR

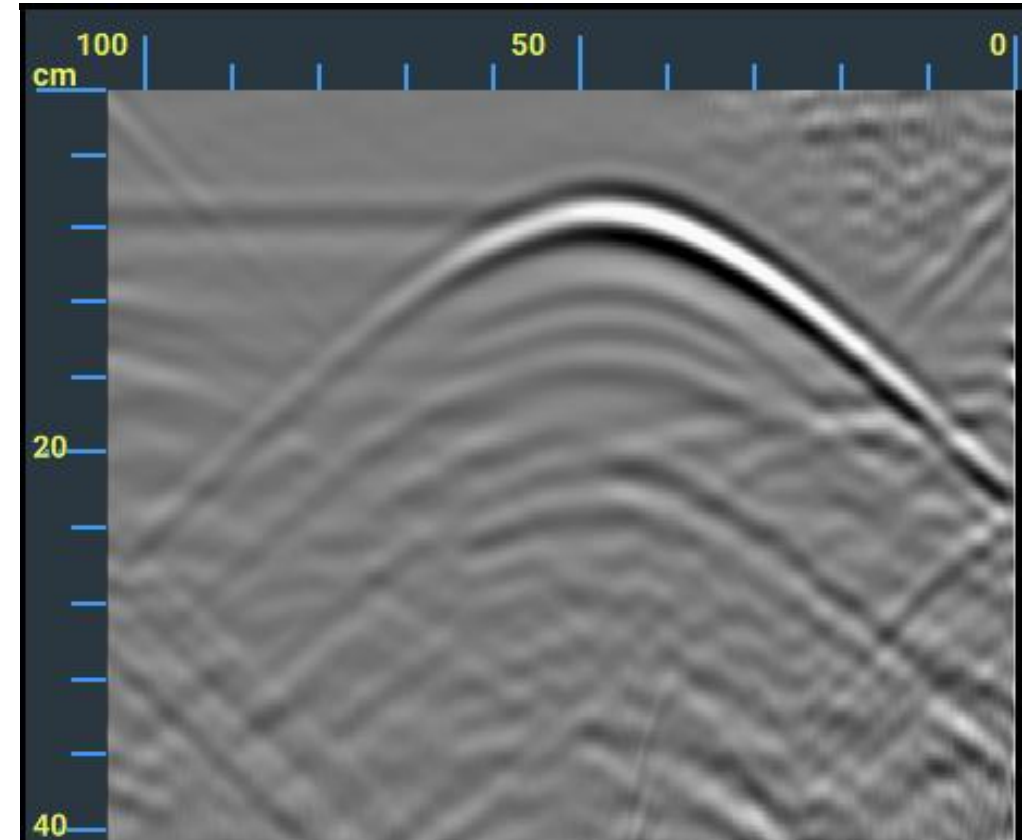
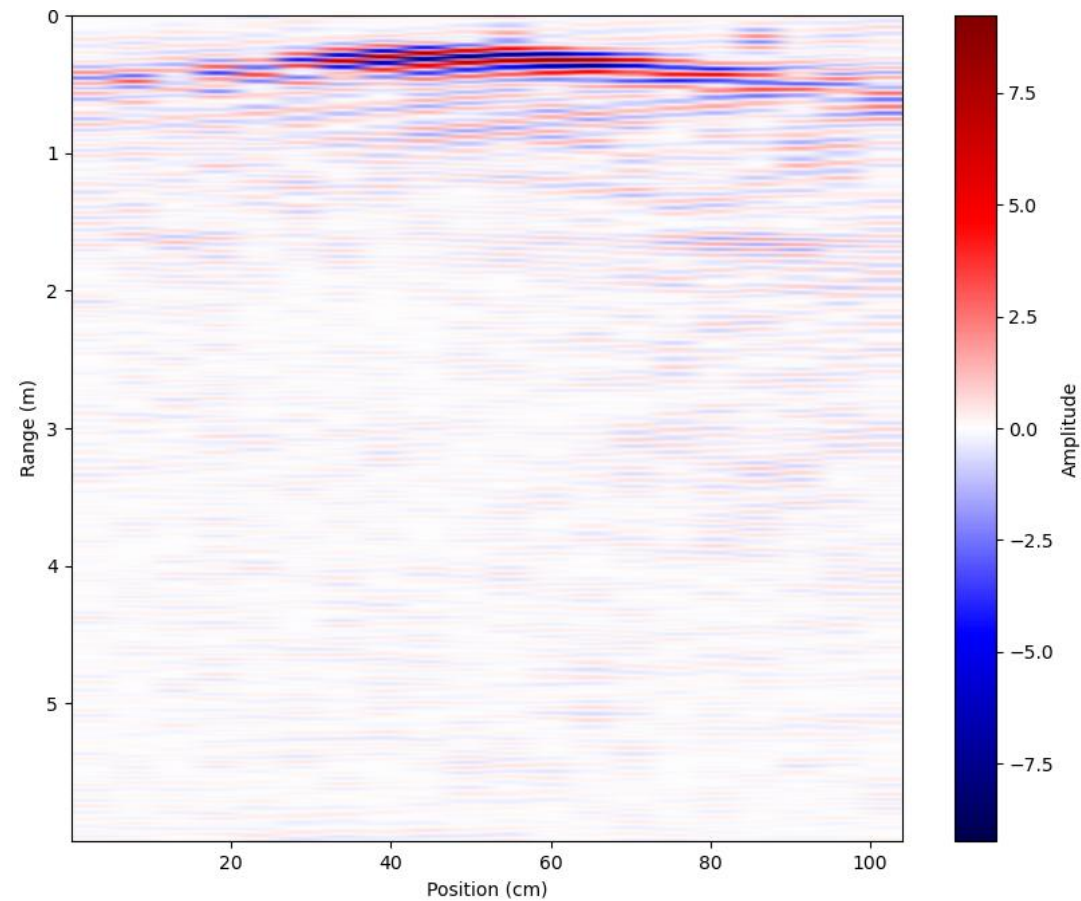


Embedded Target

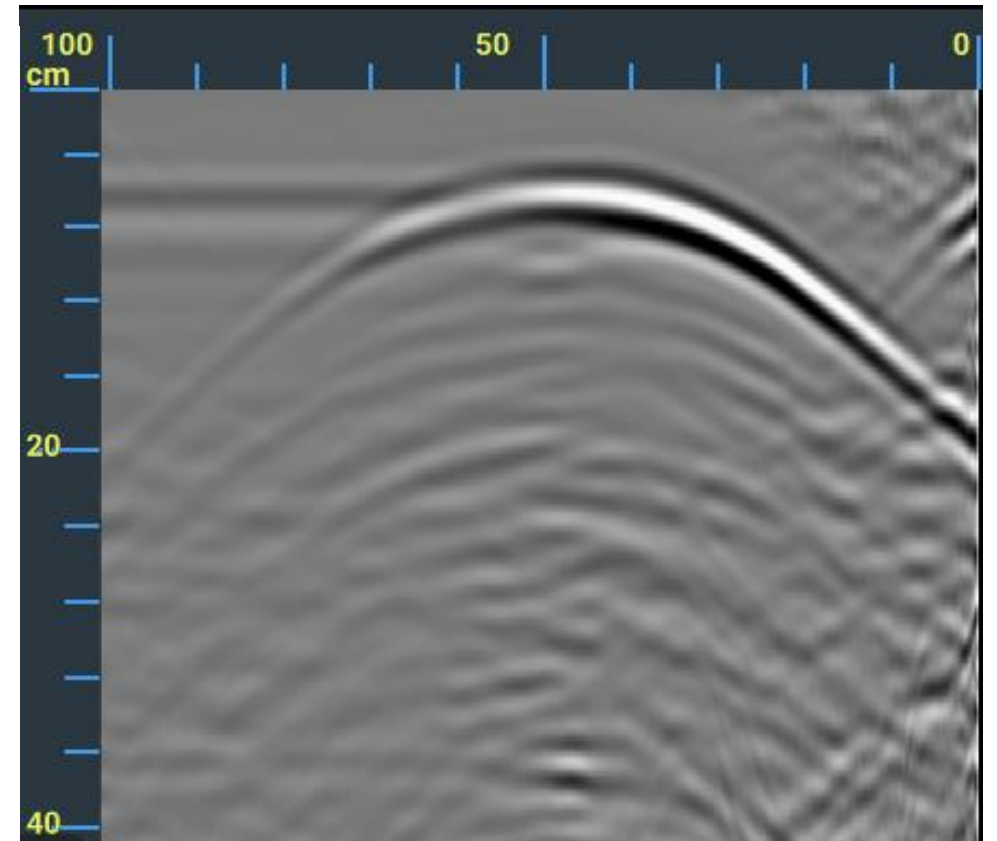
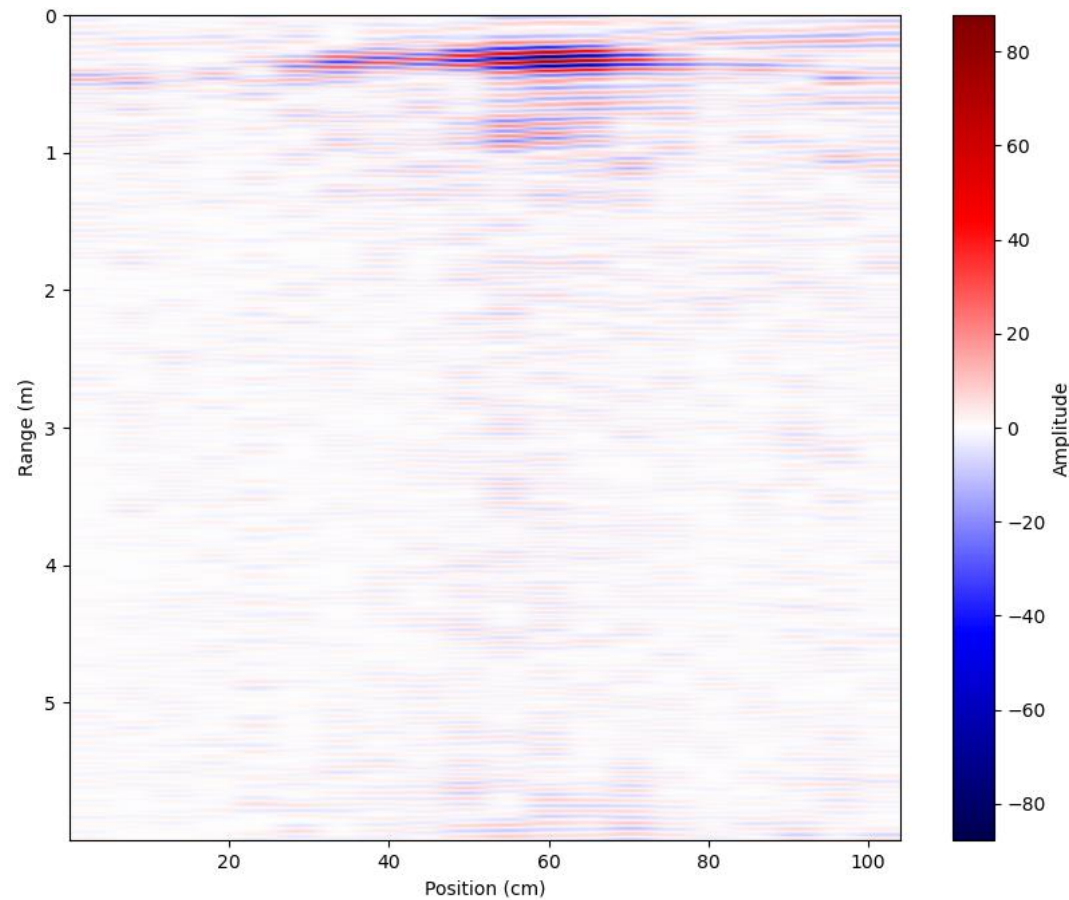


SD-GPR Test Environment

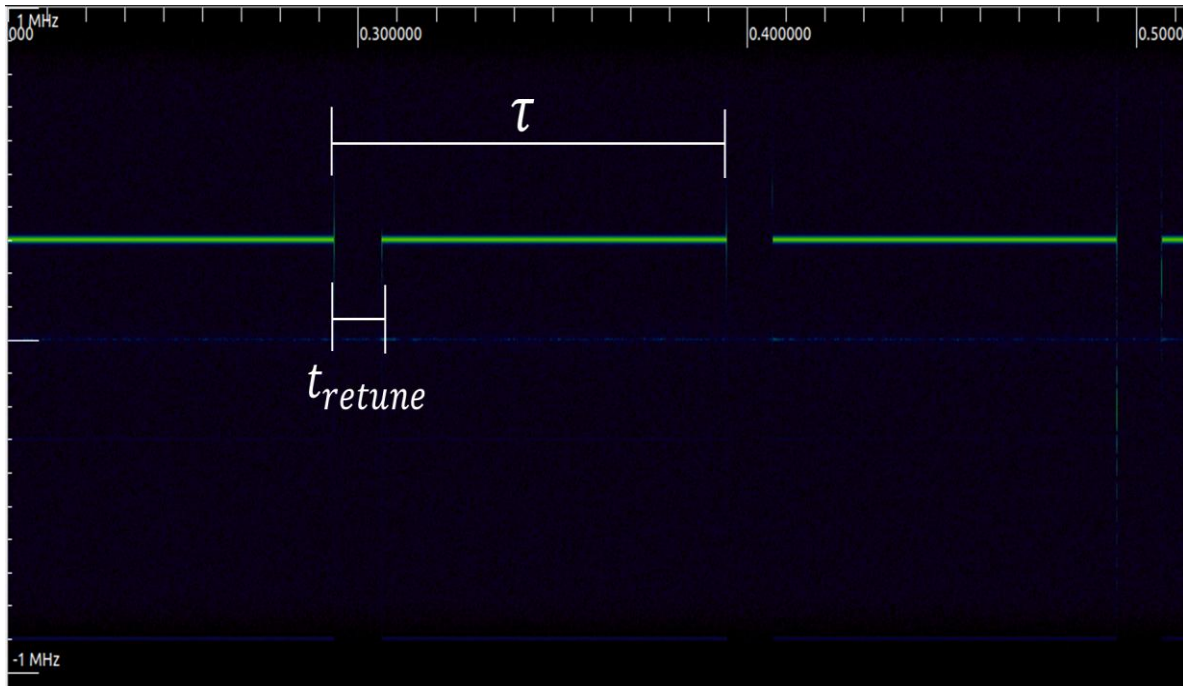
De-coupled Results – Soda Can



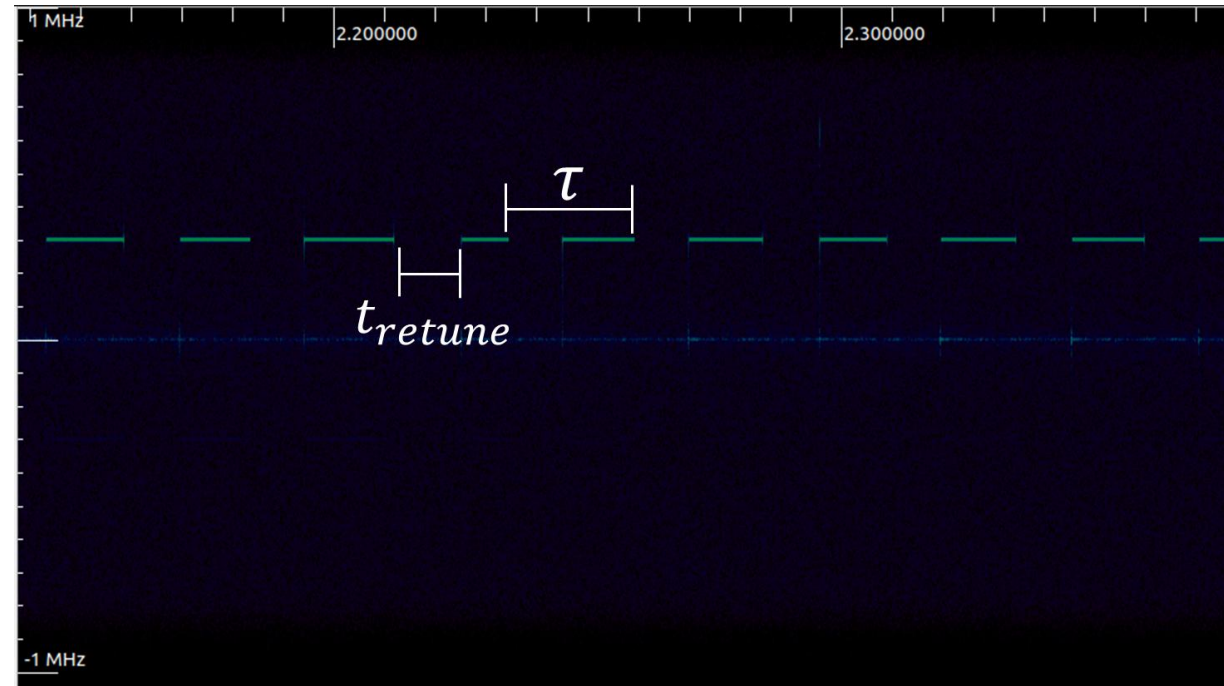
Experiment De-coupled Results – Pie Tin



Transmit Time Analysis

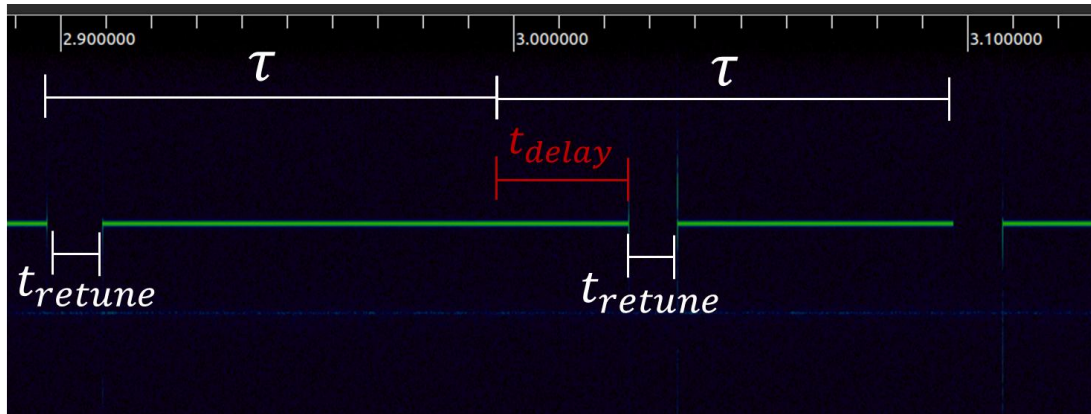


100 ms Transmit Time

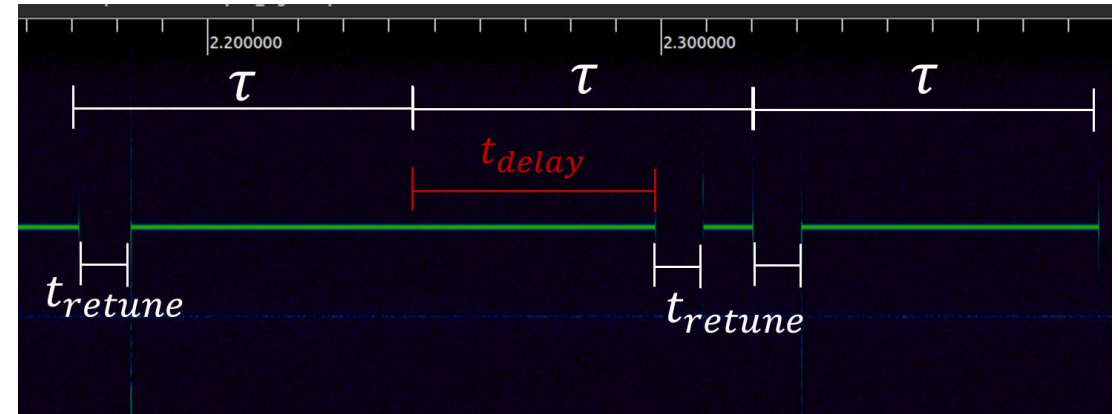


25 ms Transmit Time

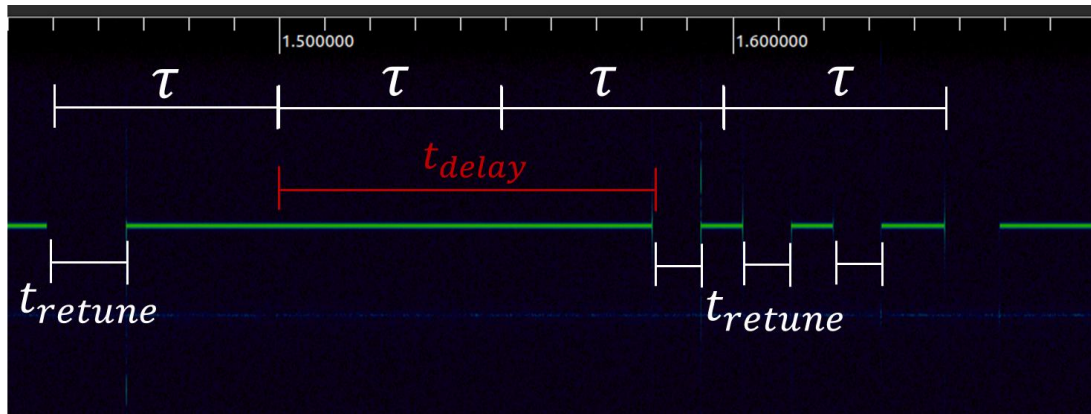
1.35 GHz Boundary



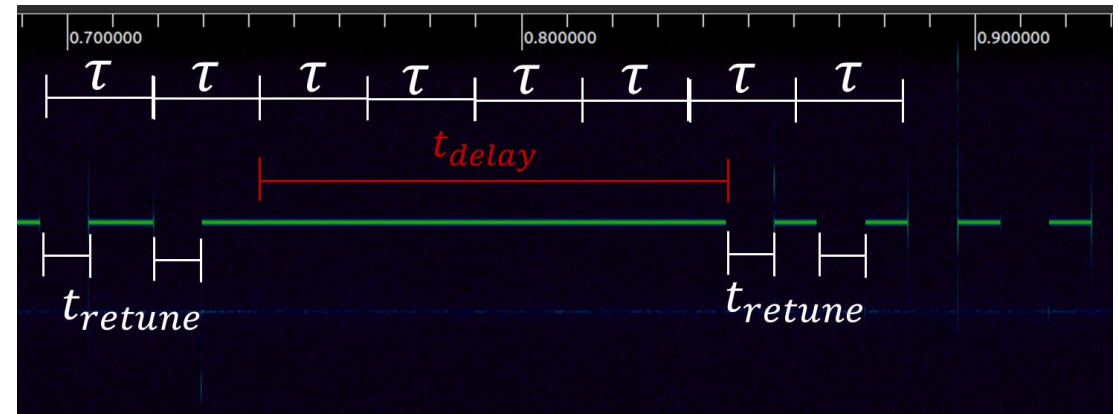
100 ms Transmit Time



75 ms Transmit Time



50 ms Transmit Time



25 ms Transmit Time



Conclusion

- Proposed SD-GPR Delivers Comparable Performance to COTS GPR
- SDR Shows Promise as an Alternative
 - Cost Effective
 - Flexible
- Future Work:
 - Addressing Retune Issues
 - Refine Static Clutter Removal
 - Real-Time Display
 - Wireless Interface

GPR	Target	Lateral	Depth	e_d	$\overline{e_d}$
COTS	Pie Tin	42 cm	5 cm	13 cm	11.5 cm
	Soda Can	46 cm	6 cm	10 cm	
SD-GPR	Pie Tin	55 cm	25 cm	11 cm	9 cm
	Soda Can	55 cm	20 cm	7 cm	



References

- [1] D. J. Daniels, Ground Penetrating Radar - 2nd Edition. The Institution of Electrical Engineers, London, United Kingdom, 2004.
- [2] D. Šipoš and D. Gleich, “A lightweight and low-power uav-borne ground penetrating radar design for landmine detection,” *Sensors*, vol. 20, no. 8, 2020.
- [3] S. Prager and M. Moghaddam, “Application of ultra-wideband synthesis in software defined radar for uav-based landmine detection,” in *IGARSS2019 - 2019 IEEE International Geoscience and Remote Sensing Symposium*, pp. 10115–10118, 2019.
- [4] S. Prager, G. Sexstone, D. McGrath, J. Fulton, and M. Moghaddam, “Snow depth retrieval with an autonomous uav-mounted software-defined radar,” *IEEE Transactions on Geoscience and Remote Sensing*, vol. 60, pp. 1–16, 2022.
- [5] J. Marimuthu, K. S. Bialkowski, and A. M. Abbosh, “Software-defined radar for medical imaging,” *IEEE Transactions on Microwave Theory and Techniques*, vol. 64, no. 2, pp. 643–652, 2016.
- [6] J. M. Weiss, “Continuous-wave stepped-frequency radar for target ranging and motion detection,” in *The Midwest Instruction and Computing Symposium*, 2009.
- [7] R. G. Lyons, “A quadrature signals tutorial: Complex, but not complicated.” <https://www.dsprelated.com/showarticle/583.php>, 2008. Accessed: 2025-08-20.
- [8] R. Persico, *Introduction to Ground Penetrating Radar: Inverse Scattering and Data Processing*. Hoboken, NJ: Wiley-IEEE Press, 2014.
- [9] M. A. Richards, *Fundamentals of Radar Signal Processing*. New York: McGraw-Hill Education, 2nd ed., 2014.

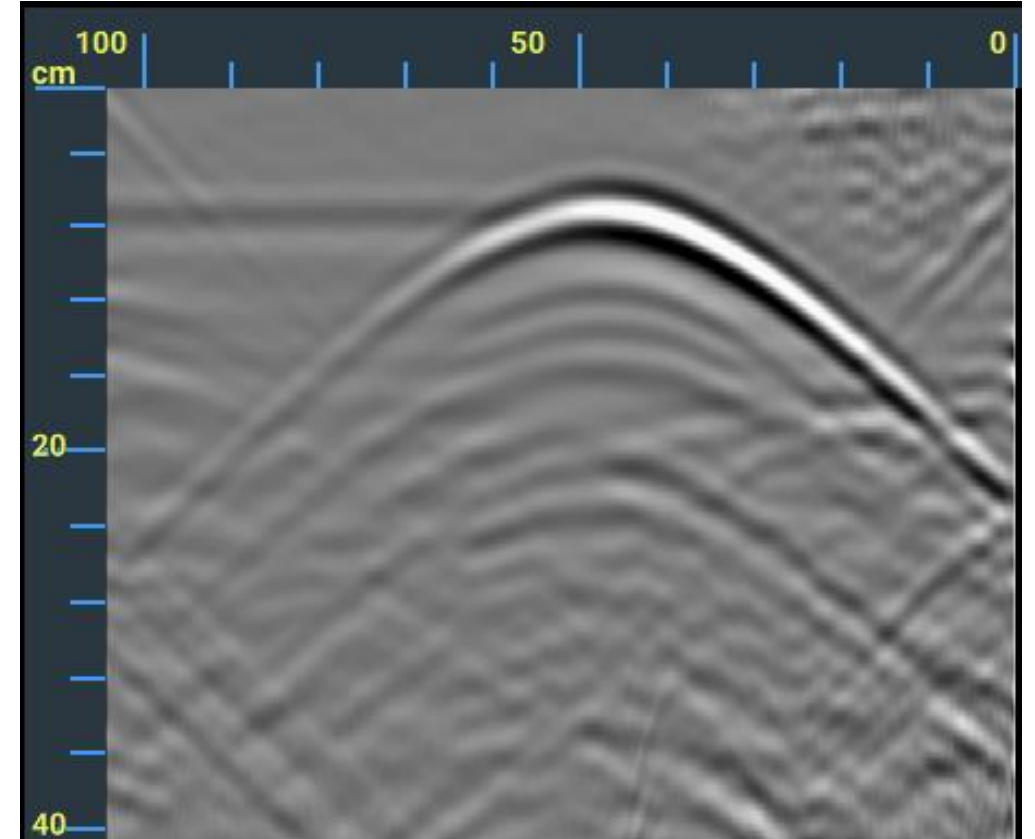
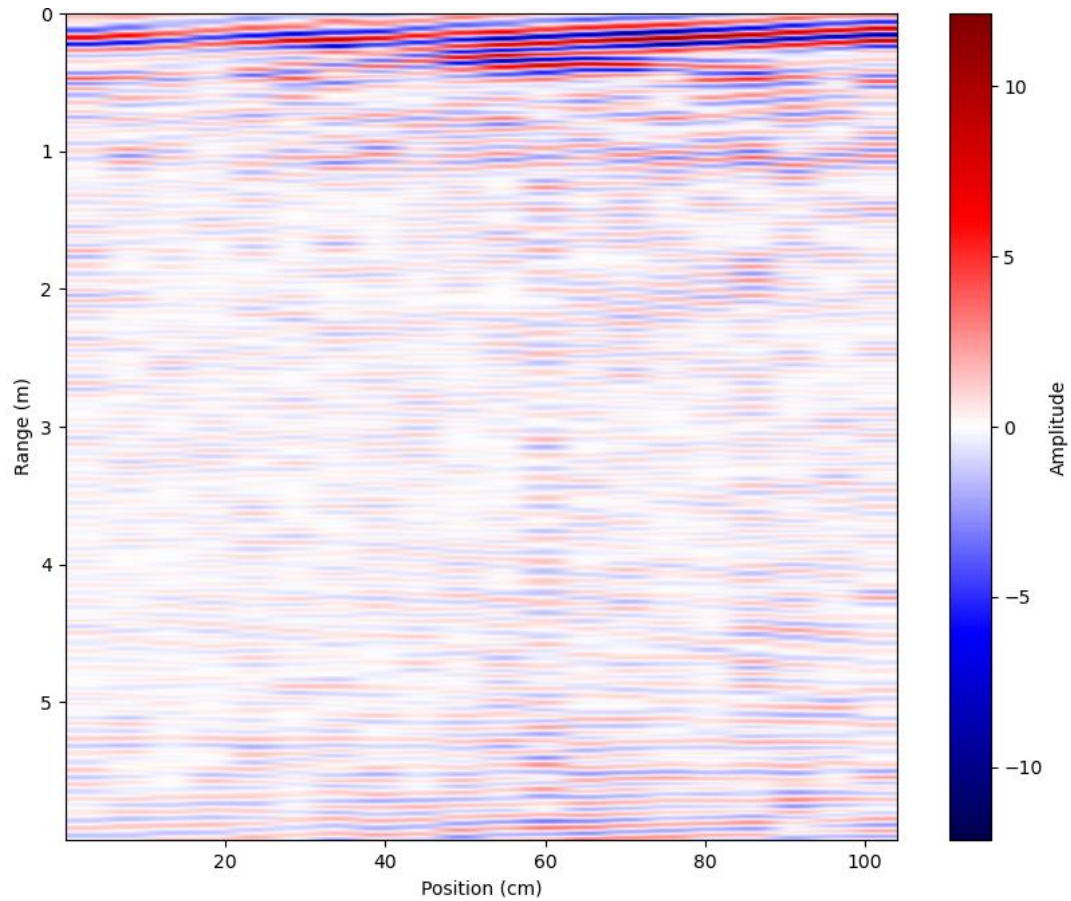


References

- [10] C. Warren, A. Giannopoulos, and I. Giannakis, “gprmax: Open sourcesoftware to simulate electromagnetic wave propagation for ground penetrating radar,” Computer Physics Communications, vol. 209, pp. 163–170, 2016.
- [11] C. Warren, A. Giannopoulos, and I. Giannakis, “gprmax: Electromagnetic simulation software.” <https://www.gprmax.com/>, 2025. Accessed:2025-04-24.
- [12] S. Prager, T. Thrivikraman, M. Haynes, J. Stang, D. Hawkins, andM. Moghaddam, “Ultra-wideband synthesis for high-range resolution software defined radar,” in 2018 IEEE Radar Conference (Radar-Conf18), pp. 1089–1094, 2018.
- [13] D. J. Daniels, W. van Verre, F. Podd, and A. J. Peyton, “Antenna design considerations for ground penetrating radar landmine detection,” IEEETransactions on Antennas and Propagation, vol. 70, no. 6, pp. 4273–4286, 2022.
- [14] C. H. J. Jenks and S. Pennock, “The use of a software defined radio asan ofdm gpr,” in 2017 9th International Workshop on Advanced Ground Penetrating Radar (IWAGPR), pp. 1–4, 2017.
- [15] miek, “Inspectrum: A tool for analyzing captured radio signals.” <https://github.com/miek/inspectrum>, 2025. Accessed: 2025-08-30.
- [16] Nuand, “bladerf: Software, firmware, and hdl for the bladerf sdr plat-form.” <https://github.com/Nuand/bladeRF>, 2025. Accessed: 2025-08-20.
- [17] Nuand, libbladeRF Documentation, Version 2.5.0. Nuand LLC, 2025.Accessed: 2025-08-20.
- [18] C. Gentile, Application of Radar Technology to Deflection Measurement and Dynamic Testing of Bridges. 01 2010.



Initial Results – Soda Can



Initial Results – Pie Tin

