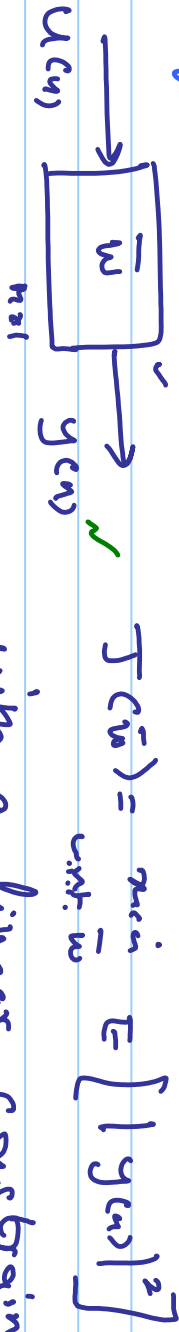


Example: linearly constrained Minimum-Variance Filter (Barn-Finery)



with a linear constraint

$$y(n) = W^H \bar{w} u(n)$$

$$J(\bar{w}) = \bar{w}^H R_{uu} \bar{w}$$

with a linear constraint

$$a^H \bar{w} = g$$

desired response → "look" direction

$$R_{uu} = E[\bar{u} \bar{u}^H]$$

lagrange multiplier technique

New var  
 $f_{w, \lambda}(\bar{w}, \bar{\lambda}) = J(\bar{w}) + Re \left[ \lambda^* (\bar{w}^H \bar{a} - g) \right]$   $\lambda \rightarrow$  Lagrangian  
 $f_{w, \lambda}(\bar{w}, \bar{\lambda}) = J(\bar{w}) + \bar{\lambda}^H R \bar{w}$

$\rightarrow \nabla_w J = 2R\bar{w} + \lambda^* \bar{a} = 0 \Rightarrow$

$\bar{w}_{opt} = -\frac{\lambda^*}{2} R^{-1} \bar{a}$

To eliminate  $\lambda$ , we use

$\nabla_{\bar{\lambda}} J(\bar{w}, \bar{\lambda}) = g^*$

$\bar{w}_0^H \bar{a} = g$  use this in (1)  
 $\bar{a}^H \bar{w}_0 = g^*$

$\lambda = \frac{-2g}{\bar{a}^H R^{-1} \bar{a}}$

$(R^{-1})^H = R^{-1}$

$$\bar{w}_0 = \frac{g^* R^{-1} \bar{d}}{\bar{d}^H R^{-1} \bar{d}}$$

$\theta_d \rightarrow$  desired 'look' dirn

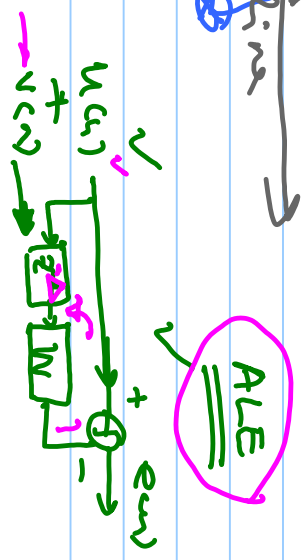
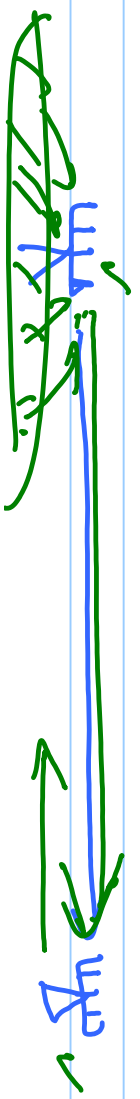
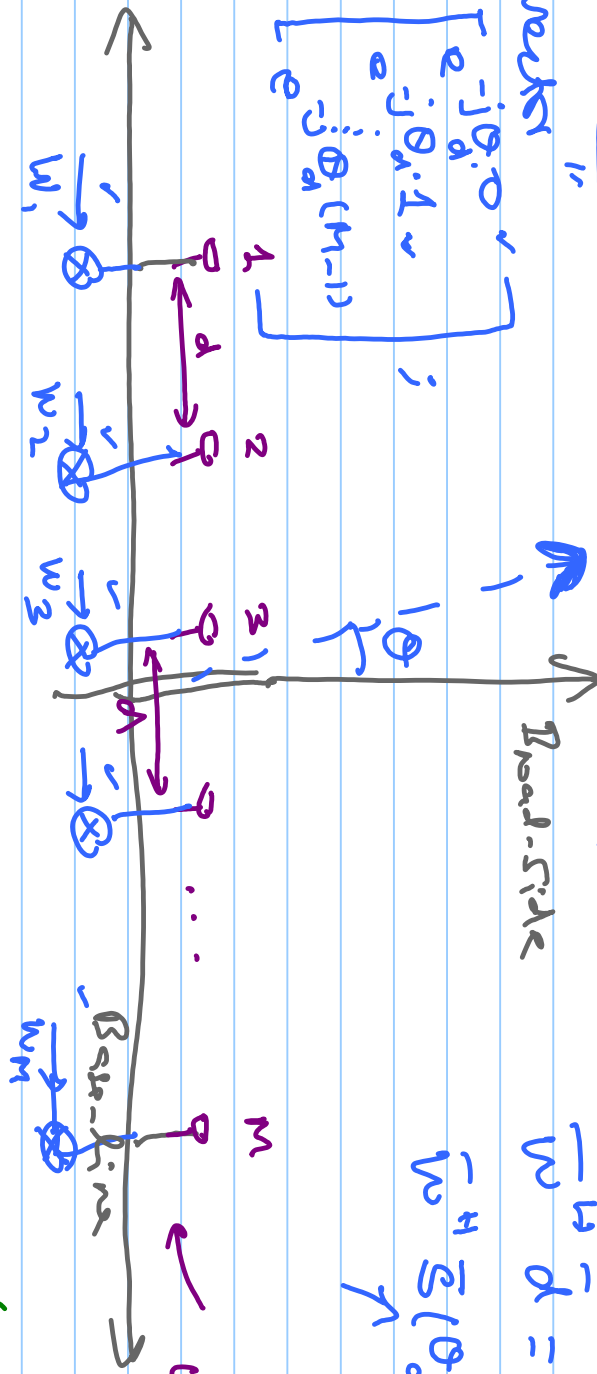
$$\bar{w}^H \bar{d} = g$$

$$\bar{w}^H \bar{s}(\theta_d) = g$$

$w_i \rightarrow r e^{j\theta}$

Steering vector

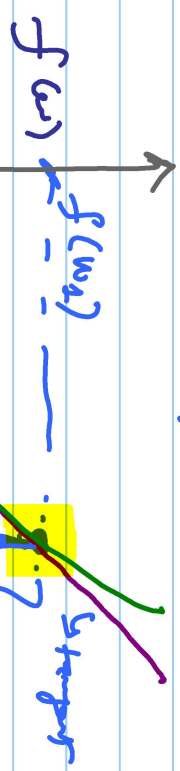
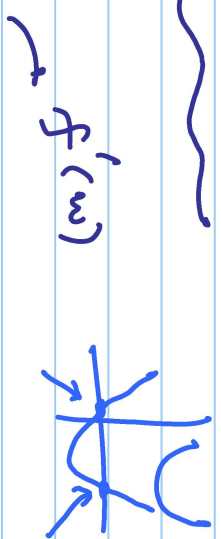
$$\bar{s}(\theta_d) = \begin{bmatrix} e^{-j\theta_d \cdot 0} \\ e^{-j\theta_d \cdot 1} \\ \vdots \\ e^{-j\theta_d \cdot (M-1)} \end{bmatrix}$$



den  $\rightarrow$  EA

# Newton's Method & Steepest Descent

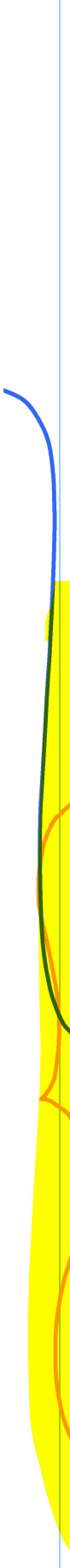
Let  $f(w)$  be a function of  $w \leftarrow \bar{w}$



To fit root of  $f(w) = 0$

$$\text{slope } f'(w_1) = \frac{f(w_1) - 0}{w_1 - w_2}$$

$$w_2' = w_1 - \left( \frac{f(w_1)}{f'(w_1)} \right)$$



$$w_{k+1} = w_k - \left( \frac{1}{f'(w_k)} \right) \cdot f(w_k), \quad k=1, 2, 3, \dots$$

LMHSE 1-step convergence !!



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