Contents

Contents vii

List of Figures ix

1 Introduction 1
1.1 Motivation 2
1.2 Objective 3
1.3 Dissertation Organization 4

2 Localization 5
2.1 Introduction 5
2.2 Components of Localization Systems 5
2.3 Classification of Localization Protocols 6
2.3.1 Range-based Methods 7
2.3.1.1 Received Signal Strength Indicator (RSSI) 7
2.3.1.2 Time Difference of Arrival(TDoA) 7
2.3.1.3 Time of Arrival (AoA) 8
2.3.2 Position Estimation 8
2.3.2.1 Trilateration and Multilateration 9
2.3.2.2 Triangulation 9
2.3.3 Range-free Methods 10
2.3.3.1 Ad-hoc Positing System(APS) 10
2.3.3.2 Point-in-Triangulation Test 11
2.4 Flip ambiguities in WSN localization 12
2.5 Discussion 13

3 Related Works 14
3.1 Introduction . . . 14
3.2 Path Planning . . . 14
3.3 Path Planning for a Mobile Anchor . . . 16
3.3.1 SCAN . . . 16
3.3.2 DOUBLE SCAN . . . 16
3.3.3 HILBERT . . . 17
3.4 Path Planning for a Group of Mobile Anchor . . . 18
3.5 Discussion . . . 18

4 Proposed Work 19
4.1 System Model and Assumption . . . 19
4.1.1 Optimal beacon point selection . . . 19
4.2 Proposed Mobile anchor Trajectory . . . 20
4.2.1 Random Deployment . . . 20
4.2.2 Grid Deployment . . . 20
4.3 Proposed algorithm . . . 21
4.3.1 Path length . . . 22
4.4 Performance Evaluation . . . 22
4.4.1 Simulation Settings . . . 22
4.4.2 Simulation Results . . . 23
4.4.2.1 Localization errors . . . 24
4.5 Challenges exist when implementing localization in WSN . . . 24

5 Conclusion and Future Work 26
5.1 Conclusion . . . 26
5.2 Future Work . . . 26

Bibliography 29

List of Figures

2.1 Components of localisation Systems 6
2.2 classification of localization protocols 6
2.3 Range base methods 9
2.4 Localization using trilateration 10
2.5 Trangulation 10
2.6 DV-hop correction example 11
2.7 Area based APIT algorithm overview 12
2.8 Flip ambiguity 13

3.1 One mobile anchor moving in S-shaped trajectory 15
3.2 a)SCAN,b)DOUBLE SCAN,c)HILBERT 17
3.3 Group of Mobile Anchor Nodes Network Model 18

4.1 Beacon point selection 20
4.2 Sensor nodes are randomly deployed and a mobile anchor moving in equilateral triangle trajectory 21
4.3 Grid based deployment of nodes and a mobile anchor moving in equilateral triangle trajectory 21
4.4 Trilateration based localization 24
4.5 Grid based deployment and a mobile anchor(blue coloured) node moves around the region and localized all nodes(red coloured) . . 24
4.6 localization vs number of nodes 25

.1 Trilateration 27