International Institute of Information Technology Bangalore

SIGNAL PROCESSING

Signal processing project

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0.1 Introduction

GPS (Global Positioning System) and IMU (Inertial Measurement Unit) are two different technologies used for determining the position of an object or a person. While both technologies can be used for distance calculation, they work differently and have their own advantages and limitations.

0.2 GPS

GPS uses a network of satellites orbiting the Earth to determine the location of an object. The GPS receiver on the object picks up signals from multiple satellites and uses the information to calculate its location. GPS is highly accurate and can provide location information with an error of just a few meters

0.3 IMU

On the other hand, an IMU uses sensors to measure the acceleration and rotation of an object. By integrating these measurements over time, it can determine the object's position and orientation. IMUs are commonly used in vehicles and drones, where GPS signals may not be reliable or available. However, IMUs are prone to accumulating errors over time, which can lead to significant inaccuracies in the distance calculations.

0.4 Python code to find distance using GPS data

```
import math
   fileName = input("Please enter the file name: ")
   rawData = open(fileName, "r")
   listOfLines = rawData.readlines()[1:]
   coordinates = []
6
   for line in listOfLines:
       data = line.split(",")
9
       coordinates.append([float(data[2]), float(data[3])])
10
11
   totalDistance = 0
12
13
14
   for i in range(1, len(coordinates)):
15
       x1, y1 = coordinates[i-1]
16
       x2, y2 = coordinates [i-0]
17
18
       distanceX = (x2-x1)*111045
19
       distanceY = (y2-y1)*87870.18
20
21
       distanceT = math.sqrt(distanceX*2 + distanceY*2)
22
       totalDistance += distanceT
23
24
25
  #Printing Required Data
```

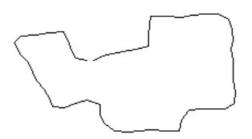
```
print("Total Distance covered(in m) = ", totalDistance)
```

0.5 Python code to find path using GPS data

```
import turtle
   import math
  #Opening The File
   fileName = input("Please enter the file name: ")
   rawData = open(fileName, "r")
  #Choosing The Decimation Level
   stepSize = int(input("Decimate The Input By Factor of: "))
9
10
  #Reading The Contents
11
   listOfLines = rawData.readlines()[1:]
12
   coordinates = []
13
14
  #Collecting Only Position Data
15
   for line in listOfLines:
16
       data = line.split(",")
       coordinates.append([float(data[2]), float(data[3])])
19
  #Turtle Screen
   pathScreen = turtle.Screen()
21
   pathScreen.title("Path Trace")
  #Intializing Turtle
   path = turtle. Turtle()
25
   path.hideturtle()
26
  #Drawing The Path
28
   for i in range(stepSize+1,len(coordinates), stepSize):
29
           #Co ordintates of Tail & Head
30
           x1, y1 = coordinates [i-stepSize]
31
           x2, y2 = coordinates [i-0]
32
33
           #Calculating Individual Components
34
           distanceX = (x2-x1)*111045
35
           distanceY = (y2-y1)*87870.18
36
37
           #Final Vector Length & Angle
38
           totalDistance = math.sqrt( distanceX*2 + distanceY*2)
39
           angleCovered = math.atan2(distanceY, distanceX)*(180/math.pi)
40
41
           #Adjusting The Angle
42
           if angleCovered >= 0:
43
                    path.setheading(angleCovered)
44
           else:
45
                    path.setheading(360+angleCovered)
46
47
```

```
#Drawing The Line
screeHeight = turtle.screensize()[1]
path.forward((totalDistance*screeHeight/(1.78*60*10))*3)
turtle.done()
```

0.6 Path travelled



0.7 Python code for finding distance using sensors

```
import pandas as pd
  import numpy as np
  import sympy as sp
  from scipy.integrate import cumtrapz
6
  # Load the accelerometer, gyroscope and magnetometer data
   accel_data = pd.read_excel('accelerometer_data.xlsx')
  gyro_data = pd.read_excel('gyroscope_data.xlsx')
10
  mag_data = pd.read_excel('magnetometer_data.xlsx')
11
12
  Time = accel data['time']
13
  Time = Time.to_numpy()
14
15
  x_axis = accel_data['ax']
```

```
x = axis = x = axis.to = numpy()*9.8
17
18
   y axis = accel data['ay']
19
   y = axis = y = axis.to = numpy()*9.8
20
   z axis = accel data['az']
22
   z = axis = z = axis.to = numpy()*9.8
23
   def cal(time, axis):
26
        stepsize =5
        axis = axis*stepsize
        prev acc = 0.0
        prev time = 0.0
        dis = 0.0
31
        j=0
        for m, n in zip (time, axis):
33
             if(j!=0):
                 \# \text{ vel1} = \text{abs}(0.5*(\text{m-prev time})(\text{n-prev acc}) + (\text{m-prev time})
35
                 (\min(n, prev\_acc)))
36
                 slope = (n-prev_acc)/(m-prev_time)
37
                 vel = (((slope)((m)2)/2)) + ((slope)(-prev_time)+prev_acc)(m))
                 - (((slope)(((prev_time)*2)/2))
39
                 + ((slope)(-prev time)+prev acc)*(prev time))
40
                 dis = dis + abs(vel*(m-prev time))
41
            prev_time = m
42
            prev acc = n
43
            i = i+1
44
        return dis
45
46
   distance arr = []
47
   distance arr.append(cal(Time, x axis))
48
   distance_arr.append(cal(Time,y_axis))
49
   distance arr.append(cal(Time, z axis))
50
   print (distance arr)
51
52
   distance = 0
53
   for k in distance arr:
        distance += k*k
55
   print(f"Total distance travelled: {np.sqrt(distance)} meters")
```

0.8 Output

Using GPS data we got the distance as 714 meters. But using the sensors data(Accelerometer, Magnetometer and gyrocope) we got the distance as 910 meters. This is because of the noise in the data.

0.9 GPS Vs IMU

Therefore, in terms of distance calculation, GPS is considered to be more accurate than an IMU. However, GPS may not always be available or reliable, especially in indoor or urban

environments where signals can be obstructed or weakened. In such cases, an IMU can provide useful information, although its accuracy may be limited over longer distances.