

Distributed Bayesian Filters for Multirobot Network Using Latest-In-and-Full-Out Exchange Protocol of Observations

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Abstract—This paper presents a measurement dissemination-based distributed Bayesian filtering (DBF) method for a multi-robot network by utilizing the Latest-In-and-Full-Out (LIFO) local exchange protocol of observations. Different from statistics dissemination approaches that transmit posterior distributions or likelihood functions, each robot under LIFO only exchanges with neighboring robots a full communication buffer consisting of latest available measurements, which reduces the transmission burden between each pair of robots from the order of environmental size to that of robot number. Under the condition of fixed and undirected topology, LIFO can guarantee non-intermittent dissemination of all observations over the network within finite time. Two types of LIFO-based DBF algorithms are then derived to estimate individual posterior density function (PDF) for static and moving target, respectively. For the static target, each robot locally fuses the newly received observations while for the moving target, a set of historical observations is stored and updated. The consistency and consensus of LIFO-based DBF are proved that estimated target position converges in probability to the true target position when the number of observations tends to infinity. The effectiveness of this method is demonstrated by numerical simulations.

Note to Practitioners—Deploying teams of robots for collecting environment information has received increasing interest in both military and civilian applications, such as surveillance, reconnaissance, search and rescue. This work focuses on distributed estimation of hidden target position in the environment. One major challenge for effective distributed estimation is the limited communication range and resource of robots. Traditional methods usually incur large transmission burden or assume that all robots can communicate with each other. This paper presents a distributed estimation scheme that is based on local exchange of sensor measurements among neighboring robots. The proposed scheme significantly reduces transmission burden and only rely on local communication, therefore suitable for applications in realistic situations. In addition, under the condition that communication between robots are bidirectional and unchanged, the proposed method ensures that all robots correctly localize the true position of the target, when enough observations are obtained. Simulations using a team of robots for localizing static and moving target are conducted to demonstrate the effectiveness of the proposed method. In future research, we will address the distributed estimation when communication between robots is time-variant and unidirectional.

Index Terms—Distributed filtering, multiagent system, consistency of estimation, consensus.

I. INTRODUCTION

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DISTRIBUTED filtering that focuses on using a group of networked robots to collectively infer environment status has been used for various applications, such as intruder detection [1], pedestrian tracking [2] and [underwater environmental monitoring](#) [3]. Several techniques have been developed for distributed filtering. For example, Olfati-Saber (2005) proposed a distributed Kalman filter (DKF) for estimating states of linear systems with Gaussian process and measurement noise [4]. Each DKF used additional low-pass and band-pass consensus filters to compute the average of weighted measurements and inverse-covariance matrices. Madhavan et al. (2004) presented a distributed extended Kalman filter for nonlinear systems [5]. This filter was used to generate local terrain maps by using pose estimates to combine elevation gradient and vision-based depth with environmental features. Gu (2007) proposed a distributed particle filter for Markovian target tracking over an undirected sensor network [6]. Gaussian mixture models (GMM) were adopted to approximate the posterior distribution from weighted particles and the parameters of GMM were exchanged via average consensus filter. As a generic filtering scheme for nonlinear systems and arbitrary noise distributions, distributed Bayesian filters (DBF) have received increasing interest during past years [7], [8], which is also the focus of this study.

The design of distributed filtering algorithms is closely related to the communication topology of multi-robot network, which can be classified into two types: fusion center (FC)-based and neighborhood (NB)-based. In the FC-based approaches, each robot uses a filter to estimate local statistics of environment status based on its own measurement. The local statistics is then transmitted (possibly via multi-hopping) to a single FC, where a global posterior distribution (or statistical moments in DKF [9]) is calculated at each filtering cycle after receiving all local information [10], [11]. In the NB-based approaches, a set of robots execute distributed filters to estimate individual posterior distribution. The consensus of individual estimates is achieved by solely communicating statistics and/or observations within local neighbors of these robots. The NB-based methods have become popular in recent years since they do not require complex routing protocols or global knowledge of the network and therefore are robust to topological changes and to link failures.

Nowadays, most studies on NB-based distributed filtering have mainly been on so-called *statistics dissemination* strategy that each robot actually exchanges statistics, including posterior distributions and likelihood functions, with neighboring robots [12]. This strategy can be further categorized into two types: leader-based and consensus-based. In the former, statistics is sequentially passed and updated along a path formed by active robots, called leaders. Only leaders perform

filtering based on its own and received measurements from local neighbors. For example, Sheng et al. (2005) proposed a multiple leader-based distributed particle filter with Gaussian Mixer for target tracking [13]. Sensors are grouped into multiple uncorrelated cliques, in each of which a leader is assigned to perform particle filtering and the particle information is then exchanged among leaders. In the consensus-based filters, every robot diffuses statistics among neighbors, via which global agreement of the statistics is achieved by using consensus protocols [9], [14], [15]. For example, Hlinka et al. (2012) proposed a distributed method for computing an approximation of the joint (all-sensors) likelihood function by means of weighted-linear-average consensus algorithm when local likelihood functions belong to the exponential family of distributions [16]. Saptarshi et al. (2014) presented a Bayesian consensus filter that uses logarithmic opinion pool for fusing posterior distributions of the tracked target [7]. Other examples can be found in [8], [17].

Despite the popularity of statistics dissemination strategy, exchanging statistics can consume high communication resources. Approximating statistics with parametric models, such as Gaussian Mixture Models [13], can reduce communication burden to some extent. Such a manipulation, however, increases the computation burden for each robot and also sacrifices the filtering accuracy due to the approximation. One potential remedy is to disseminate measurement instead of statistics among neighbors, which has not been fully exploited in robotic community so far. [One pioneering work was done by Rosencrantz et al. \(2003\), who proposed a selective communication scheme that enabled individual robots to communicate the most informative observation to other entities. However, the selection of transmitted observation requires exchange of posterior distributions, which can incur high communication cost \[18\].](#) Ribeiro et al. (2006) [proposed a distributed estimation method based on exchanging](#) quantized observations along with error-variance limits considering pragmatic signal models [19]. A recent work was conducted by Djuric et al. (2011), who proposed to broadcast raw measurements to other agents, and therefore each robot has a complete set of observations of other robots for executing particle filtering [20]. The shortcoming of aforementioned works is that their communication topologies are assumed to be a complete graph that every pair of distinct robots is directly connected by a unique edge, which is not always feasible in reality.

This paper extends existing works by introducing a Latest-In-and-Full-Out (LIFO) protocol into distributed Bayesian filters (DBF) for networked robots. Each robot is only allowed to broadcast observations to its neighbors by using single-hopping and then implements individual Bayesian filter locally after receiving transmitted observations. The main benefit of using LIFO is on the reduction of communication burden, with the transmission data volume scaling linearly with the robot number, while a statistics dissemination-based strategy can suffer from the order of environmental size. The proposed LIFO-based DBF has following properties: (1) For a fixed and undirected network, LIFO guarantees the global dissemination of observations over the network in a non-intermittent manner. (2) The corresponding DBF ensures the consistency of

estimated target position, which also implies the consensus of target PDFs.

The rest of this paper is organized as follows: The problem of distributed Bayesian filtering is formulated in Section II. The LIFO-based DBF algorithm is described in Section III, followed by the proof of consistency and consensus in Section IV. Simulation results are presented in Section V and Section VI concludes the paper.

II. PROBLEM FORMULATION

Consider a network of N robots in a bounded two-dimensional space S . Each robot is equipped with a binary sensor for environmental perception. Due to the limit of communication range, each robot can only exchange observations with its neighbors. The Bayesian filter is executed locally on each robot for target localization, based on its own and received observations via single-hopping communication.

A. Probabilistic Model of Binary Sensor

The binary sensor only gives two types of observation: 1 if the target is detected, and 0 if no target is detected. The observation of i^{th} sensor at k^{th} time step is denoted as z_k^i . The likelihood function that the target is detected is

$$P(z_k^i = 1 | x_k^T; x_k^{R,i}) \in [0, 1], \quad x_k^T \in S, \quad (1)$$

where x_k^T denotes the target position; $x_k^{R,i}$ is the robot position. Correspondingly, the likelihood function that no target is detected is

$$P(z_k^i = 0 | x_k^T; x_k^{R,i}) = 1 - P(z_k^i = 1 | x_k^T; x_k^{R,i}). \quad (2)$$

The combination of Eq. (1) and Eq. (2) forms a binary sensor model parameterized by x_k^T and $x_k^{R,i}$. The commonly used likelihood functions for binary sensor include Gaussian function [21] and step function [22].

Remark 1. Given the knowledge of current target and robot positions, current observation of each robot is conditionally independent from its own past observations and those of other robots.

Remark 2. The proposed LIFO protocol to be described in Section III is applicable for both homogeneous and heterogeneous binary sensors. A homogeneous model can simplify the analysis of completeness, while a heterogeneous model is more close to real sensing characteristics. In addition, it also works for other types of sensors, such as laser scanners and cameras.

B. Graphical Model of Communication Topology

The robot network is always assumed to be connected, i.e., there exists a path, either direct or indirect, between every pair of robots. Under this assumption, consider an undirected and fixed graph $G = (V, E)$, where $V = \{1, \dots, N\}$ represents the index set of robots and $E = V \times V$ denotes the edge set. The adjacency matrix $M = [m_{ij}]$ describes the communication topology of G :

$$m_{ij} = \begin{cases} 1 & \text{if } (i, j) \in E \\ 0 & \text{if } (i, j) \notin E \end{cases},$$

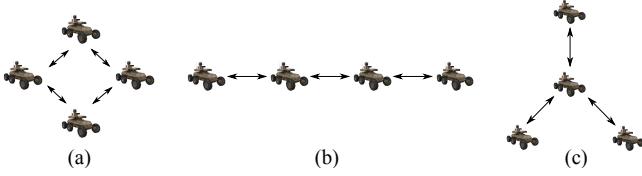


Fig. 1: Three types of topologies: (a) ring topology; (b) line topology; (c) star topology

where m_{ij} denotes the entity of adjacency matrix. The notation $m_{ij} = 1$ indicates that a communication link exists between i^{th} and j^{th} robot and $m_{ij} = 0$ indicates no communication between them.

The *direct neighborhood* of i^{th} robot is defined as $\mathcal{N}_i = \{j | m_{ij} = 1, \forall j \in \{1, \dots, N\}\}$. All the robots in \mathcal{N}_i can directly exchange information with i^{th} robot. In addition to direct neighborhood, another set called *available neighborhood* is defined as \mathcal{Q}_i , which contains indices of robots whose observations can be received by the i^{th} robot given a specific observation exchange protocol. Note that in general $\mathcal{N}_i \subseteq \mathcal{Q}_i$. Fig. 1 illustrates three types of typical topologies: ring [23], line [24], and star [25]. All of them are undirected and connected topologies.

C. Distributed Bayesian Filter for Multiple Robots

The generic distributed Bayesian filter (DBF) is introduced. Each robot has its individual estimation of posterior density function (PDF) of target position, called *individual PDF*. The individual PDF of i^{th} robot at time k is defined as $P_{pdf}^i(x_k^T | \mathbf{z}_{1:k}^i)$, where $\mathbf{z}_{1:k}^i$ denotes the set of observations by i^{th} robot and by robots in \mathcal{Q}_i that are transmitted to i^{th} robot by time k . The individual PDF is initialized as $P_{pdf}^i(x_0^T | \mathbf{z}_0^i) = P(x_0^T)$, given all available prior information including past experience and environmental knowledge. Under the DBF framework, the individual PDF is recursively estimated by two steps, i.e., prediction step and updating step.

1) *Prediction*: At time k , the prior individual PDF $P_{pdf}^i(x_k^T | \mathbf{z}_{1:k-1}^i)$ is first predicted forward by using the Chapman-Kolmogorov equation:

$$P_{pdf}^i(x_k^T | \mathbf{z}_{1:k-1}^i) = \int P(x_k^T | x_{k-1}^T) P_{pdf}^i(x_{k-1}^T | \mathbf{z}_{1:k-1}^i) dx_{k-1}^T, \quad (3)$$

where $P(x_k^T | x_{k-1}^T)$ is a Markov motion model of the target, independent of robot states. This model describes the state transition probability of the target from a prior state x_{k-1}^T to posterior state x_k^T . Note that if the target is static, such as in the application of indoor search for stationary objects [26], Markov motion model is simplified to be

$$P(x_k^T | x_{k-1}^T) = \begin{cases} 1 & \text{if } x_k^T = x_{k-1}^T \\ 0 & \text{if } x_k^T \neq x_{k-1}^T \end{cases}.$$

2) *Updating*: The i^{th} individual PDF is then updated by Bayes' formula using the set of newly received observations \mathbf{z}_k^i :

$$P_{pdf}^i(x_k^T | \mathbf{z}_{1:k}^i) = K_i P_{pdf}^i(x_k^T | \mathbf{z}_{1:k-1}^i) P(\mathbf{z}_k^i | x_k^T), \quad (4)$$

where K_i is a normalizing factor:

$$K_i = 1 / \int P_{pdf}^i(x_k^T | \mathbf{z}_{1:k-1}^i) P(\mathbf{z}_k^i | x_k^T) dx_k^T.$$

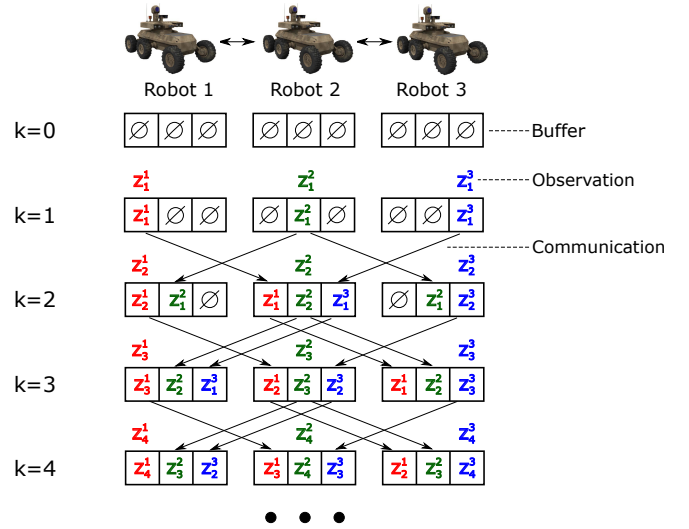


Fig. 2: Example of LIFO with three robots using line communication topology

and $P_{pdf}^i(x_k^T | \mathbf{z}_{1:k}^i)$ is called posterior individual PDF; $P(z_k^i | x_k^T)$ is the likelihood function of observation z_k^i , described in Eq. (1) and Eq. (2).

III. DISTRIBUTED BAYESIAN FILTER VIA LATEST-IN-AND-FULL-OUT PROTOCOL

This study proposes a Latest-In-and-Full-Out (LIFO) protocol for observation exchange and derives two corresponding distributed Bayesian filtering (DBF) algorithms, shorted as LIFO-DBF. The data communication in LIFO uses synchronized step as the execution of DBF. In each step, LIFO only allows single-hopping communication within the direct neighborhood, but with the ability to broadcast observations of each robot to any other agents after a finite number of steps. The individual PDF is predicted and updated in DBF after each LIFO cycle. The theoretical analysis show that LIFO-DBF can ensure the consistency and consensus of distributed estimation while requiring much less communication burden than statistics dissemination-based methods.

A. Latest-In-and-Full-Out (LIFO) Protocol

Under LIFO, each robot contains a communication buffer (CB) to store its latest knowledge of observations of all robots:

$$\mathbf{z}_k^{CB,i} = [z_{k_1^i}^1, \dots, z_{k_N^i}^N],$$

where $z_{k_j^i}^j$ represents the observation made by j^{th} robot at time k_j^i . Note that under LIFO, $\mathcal{Q}_i = \{1, \dots, N\} \setminus \{i\}$, which will be proved in Corollary 1. At time k , $z_{k_j^i}^j$ is received and stored in i^{th} robot CB, in which k_j^i is the latest observation time of j^{th} robot available to i^{th} robot. Due to the communication delay, $k_j^i < k, \forall j \neq i$ and $k_i^i = k$ always holds. The **LIFO protocol** is stated in Algorithm 1.

Fig. 2 illustrates the LIFO cycles with 3 robots using a line topology. Two facts can be noticed in Fig. 2: (1) all robot CBs are filled within 3 steps, which means under LIFO each robot

Algorithm 1 LIFO Protocol

(1) Initialization: The CB of i^{th} robot is initialized when $k = 0$:

$$z_{k_j^i}^j = \emptyset, \quad k_j^i = 0, \quad j = 1, \dots, N.$$

(2) At k^{th} step for i^{th} robot :

(2.1) Receiving Step:

The i^{th} robot receives all CBs of its direct neighborhood \mathcal{N}_i . The received CBs are totally $|\mathcal{N}_i|$ groups, each of which corresponds to the $(k-1)$ -step CB of a robot in \mathcal{N}_i . The received CB from l^{th} ($l \in \mathcal{N}_i$) robot is denoted as

$$\mathbf{z}_{k-1}^{CB,l} = [z_{(k-1)_1^l}^1, \dots, z_{(k-1)_N^l}^N], \quad l \in \mathcal{N}_i.$$

(2.2) Observation Step:

The i^{th} robot updates $z_{k_j^i}^j$ ($j = i$) by its own observation at current step:

$$z_{k_j^i}^j = z_{k_j^i}^i, \quad k_j^i = k, \quad \text{if } j = i.$$

(2.3) Comparison Step:

The i^{th} robot updates other elements of its own CB, i.e., $z_{k_j^i}^j$ ($j \neq i$), by selecting the latest information among all received CBs from \mathcal{N}_i . For all $j \neq i$,

$$l_{\text{latest},j} = \underset{l \in \mathcal{N}_i \cup \{i\}}{\operatorname{argmax}} \left\{ (k-1)_j^l \right\}$$

$$z_{k_j^i}^j = z_{(k-1)_j^{l_{\text{latest},j}}}^j, \quad k_j^i = (k-1)_j^{l_{\text{latest},j}}.$$

(2.4) Sending Step:

The i^{th} robot broadcasts its updated CB to all of its neighbors defined in \mathcal{N}_i .

(3) $k \leftarrow k + 1$ until stop.

has a maximum delay of 2 steps for receiving observations from other robots; (2) once filled, CBs are updated non-intermittently, which means each robot continuously receives new observations of other robots. Extending the two facts to a network of N robots, we have the following proposition:

Proposition 1. For a fixed and undirected network of N robots, LIFO uses the shortest path(s) between i^{th} and j^{th} robot to exchange observation, the length of which is the delay $\tau_{i,j}$ between these two robots.

Proof. Without loss of generality, assume that there is a unique shortest path between i and j , denoted by $T_{n^*}^{j,i} = (v_1, \dots, v_{n^*})$, with $v_1 = j, v_{n^*} = i, v_{m+1} \in \mathcal{N}_{v_m}$. Then, the distance between i and j is $d(j,i) = n^* - 1$. The following mathematical induction proves Proposition 1.

Step (1): When $d(j,i) = 1$, $j \in \mathcal{N}_i$ and j can directly send z_k^j to i . Then z_k^j is stored in i^{th} CB at time $k+1$, i.e., $\tau_{i,j} = 1$. Proposition 1 holds for $d(j,i) = 1, \forall i, j \in \{1, \dots, N\}$.

Step (2): Suppose that Proposition 1 holds for $d(j,i) = s, s \geq 2, \forall i, j \in \{1, \dots, N\}$. Then for $d(j,i) = s+1$, i.e., $n^* = s+2$, by the Bellman's principle of optimality, the path $T_{n^*-1}^{j,i} = (v_1, \dots, v_{n^*-1})$ is a shortest path between j and i , where $v_{n^*-1} = l$ and $i \in \mathcal{N}_l$. The assumption that Proposition 1 holds for $d(j,i) = s$ implies that z_k^j is

received and stored in l^{th} robot's CB at time $k+s$. Since $i \in \mathcal{N}_l$, i^{th} robot receives z_k^j at $k+s+1$. For any other path $T_n^{j,i} = (v_1, \dots, v_n)$ with $n > n^*$, z_k^j cannot be received by i earlier than $k+s+1$. Therefore $\tau_{i,j} = s+1$. This proves the Proposition 1 for $d(j,i) = s+1$. \square

Corollary 1. For the same topology in Proposition 1, all elements in $\mathbf{z}_k^{CB,i}$ under LIFO become filled when $k \geq N$, i.e., $\mathcal{Q}_i = \{1, \dots, N\} \setminus \{i\}$.

Proof. In a network of N robots, the maximal length of shortest paths is no greater than $N-1$. Based on Proposition 1, $\tau_{i,j} \leq N-1$ and thus all elements of $\mathbf{z}_k^{CB,i}$ become filled when $k \geq N$. \square

Corollary 2. For the same topology in Proposition 1, once all elements in $\mathbf{z}_k^{CB,i}$ are filled, the updating of each element is non-intermittent.

Proof. For a network with fixed topology, shortest path(s) between any pair of nodes are fixed. Therefore, based on Proposition 1, $\tau_{i,j}$ is constant and the updating of each element in $\mathbf{z}_k^{CB,i}$ is non-intermittent. \square

Remark 3. Compared to statistics dissemination, LIFO is generally more communication-efficient for distributed filtering. To be specific, consider an $M \times M$ grid environment with a network of N robots, the transmitted data of LIFO between each pair of robots are only the CB of each robot and corresponding robot positions where observations were made, the length of which is $O(N)$. On the contrary, the length of transmitted data for a statistics dissemination approach that transmits unparameterized posterior distributions or likelihood functions is $O(M^2)$, which is in the order of environmental size. Since M is generally much larger than N in applications such as target localization, LIFO requires much less communication resources.

B. Algorithm of LIFO-DBF for Static Target

This section derives the LIFO-DBF algorithm for localizing a static target. Each robot stores last-step individual PDF, i.e., $P_{pdf}^i(x^T | \mathbf{z}_{1:k-1}^i)$. According to Corollary 2, $\mathbf{z}_k^i = \mathbf{z}_k^{CB,i}$ and $\mathbf{z}_{1:k}^i = \mathbf{z}_{1:k}^{CB,i} = [z_{1:k_1^i}^1, \dots, z_{1:k_N^i}^N]$. The assumption of static target can simplify the Bayesian filter as the prediction step becomes unnecessary. Therefore, the i^{th} individual PDF is only updated by

$$P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i) = K_i P_{pdf}^i(x_k^T | \mathbf{z}_{1:k-1}^i) P(\mathbf{z}_k^i | x_k^T)$$

$$= K_i P_{pdf}^i(x^T | \mathbf{z}_{1:k-1}^i) \prod_{j=1}^N P(z_{k_j^i}^j | x^T), \quad (5)$$

where

$$K_i = 1 / \int P_{pdf}^i(x^T | \mathbf{z}_{1:k-1}^i) \prod_{j=1}^N P(z_{k_j^i}^j | x^T) dx^T.$$

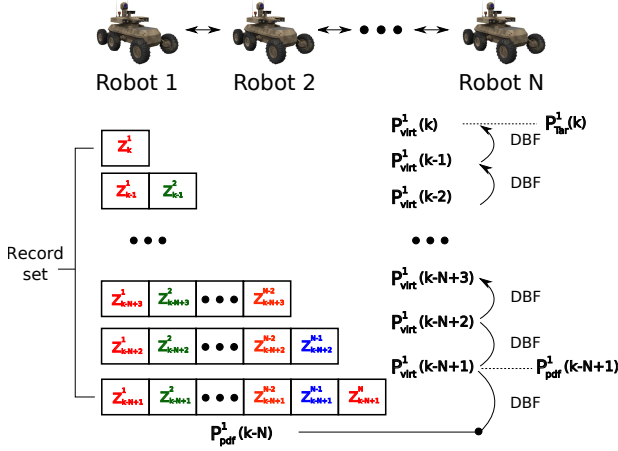


Fig. 3: Example of LIFO-DBF for 1st robot at time k . Networked robots take a line topology, shown in the top. The stored individual PDF is $P^1_{pdf}(k-N)$. The robot first calculates $P^1_{virt}(k-N+1)$ using DBF and stores it as $P^1_{pdf}(k-N+1)$. Repeating DBF until obtaining $P^1_{pdf}(k)$, which is then used as the individual PDF estimation of 1st robot at time k . In this example, $\Omega^1_\xi = \{1, 2, \dots, N+1-\xi\}$, $\xi = 1, \dots, N$.

C. Algorithm of LIFO-DBF for Moving Target

This section derives the LIFO-DBF for localizing a moving target. Instead of storing last-step PDF, at time k each robot maintains an individual PDF of time $(k-N)$ and a collection of historical observations, called the *record set*, from time $(k-N+1)$ to k . The i^{th} individual PDF is then alternatively predicted and updated by using aforementioned Bayesian filter (Eq. (3) and Eq. (4)) from $(k-N)$ to k . Fig. 3 illustrates the LIFO-DBF procedure for the 1st robot as an example. With a line topology, the record set of 1st robot is shown as a triangle.

Let Ω^i_ξ ($\xi = 1, \dots, N$) denote the index set of robots whose observation at time $(k-N+\xi)$ is stored in i^{th} robot's record set. The **LIFO-DBF algorithm** for moving target is then stated in Algorithm 2.

Remark 4. For the static target, each robot only needs current step CB to update individual PDFs. Therefore, besides storing individual PDF with size $O(M^2)$, only current-step CB is stored in robot memory and all historical CBs can be discarded, which means that the size of occupied memory is $O(N+M^2)$. On the contrary, for the moving target, each robot needs to store a triangular matrix of historical observation with size of $O(N^2)$ and an individual PDF with size $O(M^2)$, which means that the size of occupied memory in each robot is $O(M^2 + N^2)$.

IV. PROOF OF CONSISTENCY AND CONSENSUS

This section proves consistency and consensus of LIFO-DBF. Only proofs for localizing static target are presented, including both static and moving robots. The proof of LIFO-DBF for moving target is similar to that of static target by considering the dynamic model of the target, which is omitted here.

Algorithm 2 LIFO-DBF Algorithm for Moving Target

For i^{th} robot at k^{th} step:

After updating CB by Algorithm 1,

(1) The stored individual PDF for time $(k-N)$ is:

$$P^i_{pdf}(x^T_{k-N} | z^1_{1:k-N}, \dots, z^N_{1:k-N})$$

(2) Initialize a virtual PDF by assigning the individual PDF to it:

$$P^i_{virt}(x^T_{k-N}) = P^i_{pdf}(x^T_{k-N} | z^1_{1:k-N}, \dots, z^N_{1:k-N})$$

(3) From $\xi = 1$ to N , repeat two steps of Bayesian filtering:

(3.1) Prediction

$$P^{pre}_{virt}(x^T_{k-N+\xi}) = \int P(x^T_{k-N+\xi} | x^T_{k-N+\xi-1}) P^i_{virt}(x^T_{k-N+\xi-1}) dx^T_{k-N+\xi-1}$$

(3.2) Updating

$$P^i_{virt}(x^T_{k-N+\xi}) = K_\xi P^{pre}_{virt}(x^T_{k-N+\xi}) \prod_{j \in \Omega^i_\xi} P(z^j_{k-N+\xi} | x^T_{k-N+\xi})$$

$$K_\xi = 1 / \int P^{pre}_{virt}(x^T_{k-N+\xi}) \prod_{j \in \Omega^i_\xi} P(z^j_{k-N+\xi} | x^T_{k-N+\xi}) dx^T_{k-N+\xi}$$

(3.3) When $\xi = 1$, store the virtual PDF as the individual PDF for time $(k-N+1)$

$$P^i_{pdf}(x^T_{k-N+1} | z^1_{1:k-N+1}, \dots, z^N_{1:k-N+1}) = P^i_{virt}(x^T_{k-N+1}).$$

(4) Individual PDF of i^{th} robot at time k is $P^i_{pdf}(x^T_k | z^i_{1:k}) = P^i_{virt}(x^T_k)$.

A. Proof for static robots

Considering S is finite and x^{T*} is the true location of target, the consistency of LIFO-DBF for static robots is stated as follows:

Theorem 1. When robots are static, the estimated target position converges to the true position of target in probability using LIFO-DBF, i.e.,

$$\lim_{k \rightarrow \infty} P(x^T = x^{T*} | z^i_{1:k}) = 1, \quad i = 1, \dots, N.$$

Proof. Considering the conditional independence of observations given $x^T \in S$, the batch form of DBF at k^{th} step is:

$$P^i_{pdf}(x^T | z^i_{1:k}) = P^i_{pdf}(x^T | z^1_{1:k^i_1}, \dots, z^N_{1:k^i_N}) = \frac{P^i_{pdf}(x^T) \prod_{j=1}^N \prod_{l=1}^{k^i_j} P(z^j_l | x^T)}{\sum_{x^T \in S} P^i_{pdf}(x^T) \prod_{j=1}^N \prod_{l=1}^{k^i_j} P(z^j_l | x^T)}$$

where P^i_{pdf} is i^{th} initial individual PDF. It is known from Corollary 1 and Corollary 2 that $k-N < k^i_j \leq k$.

Comparing $P^i_{pdf}(x^T | z^i_{1:k})$ with $P^i_{pdf}(x^{T*} | z^i_{1:k})$ yields

$$\frac{P^i_{pdf}(x^T | z^i_{1:k})}{P^i_{pdf}(x^{T*} | z^i_{1:k})} = \frac{P^i_{pdf}(x^T) \prod_{j=1}^N \prod_{l=1}^{k^i_j} P(z^j_l | x^T)}{P^i_{pdf}(x^{T*}) \prod_{j=1}^N \prod_{l=1}^{k^i_j} P(z^j_l | x^{T*})}. \quad (6)$$

Take the logarithm of Eq. (6) and average it over k steps:

$$\frac{1}{k} \ln \frac{P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i)}{P_{pdf}^i(x^{T*} | \mathbf{z}_{1:k}^i)} = \frac{1}{k} \ln \frac{P_{pdf}^i(x^T)}{P_{pdf}^i(x^{T*})} + \sum_{j=1}^N \frac{1}{k} \sum_{l=1}^{k_j^i} \ln \frac{P(z_l^j | x^T)}{P(z_l^j | x^{T*})}. \quad (7)$$

Since $P_{pdf}^i(x^T)$ and $P_{pdf}^i(x^{T*})$ are bounded, then

$$\lim_{k \rightarrow \infty} \frac{1}{k} \ln \frac{P_{pdf}^i(x^T)}{P_{pdf}^i(x^{T*})} = 0. \quad (8)$$

The binary observations subject to Bernoulli distribution $B(1, p_j)$, yielding

$$P(z_l^j | x^T) = p_j^{z_l^j} (1 - p_j)^{1 - z_l^j},$$

where $p_j = P(z_l^j = 1 | x^T)$. Utilizing the facts: (1) z_l^j are conditionally independent samples from $B(1, p_j^*)$ and (2) $k - N < k_j^i \leq k$, the law of large numbers yields

$$\frac{1}{k} \sum_{l=1}^{k_j^i} z_l^j \xrightarrow{P} p_j^*, \quad \frac{1}{k} (k_j^i - \sum_{l=1}^{k_j^i} z_l^j) \xrightarrow{P} 1 - p_j^*,$$

where $p_j^* = P(z_l^j = 1 | x^{T*})$ and “ \xrightarrow{P} ” denotes “convergence in probability”. Then,

$$\frac{1}{k} \sum_{l=1}^{k_j^i} \ln \frac{P(z_l^j | x^T)}{P(z_l^j | x^{T*})} \xrightarrow{P} p_j^* \ln \frac{p_j}{p_j^*} + (1 - p_j^*) \ln \frac{1 - p_j}{1 - p_j^*}. \quad (9)$$

Note that the right-hand side of Eq. (9) achieves maximum value 0 if and only if $p_j = p_j^*$. Define

$$c(x^T) = \sum_{j=1}^N p_j^* \ln \frac{p_j}{p_j^*} + (1 - p_j^*) \ln \frac{1 - p_j}{1 - p_j^*}.$$

Considering Eq. (8) and Eq. (9), the limit of Eq. (7) is

$$\frac{1}{k} \ln \frac{P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i)}{P_{pdf}^i(x^{T*} | \mathbf{z}_{1:k}^i)} \xrightarrow{P} c(x^T). \quad (10)$$

It follows from Eq. (10) that

$$\frac{P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i)}{P_{pdf}^i(x^{T*} | \mathbf{z}_{1:k}^i) e^{c(x^T)k}} \xrightarrow{P} 1. \quad (11)$$

Define the set $\bar{X}^T = S \setminus \{x^{T*}\}$ and $c_M = \max_{x^T \in \bar{X}^T} c(x^T)$.

Then $c_M < 0$. Summing Eq. (11) over \bar{X}^T yields

$$\frac{\sum_{x^T \in \bar{X}^T} P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i) e^{[c_M - c(x^T)]k}}{P_{pdf}^i(x^{T*} | \mathbf{z}_{1:k}^i) e^{c_M k}} \xrightarrow{P} |\bar{X}^T|, \quad (12)$$

where $|\bar{X}^T|$ denotes the cardinality of \bar{X}^T .

Since $c_M < 0$, $P_{pdf}^i(x^{T*} | \mathbf{z}_{1:k}^i) e^{c_M k} \rightarrow 0$, Eq. (12) implies

$$\sum_{x^T \in \bar{X}^T} P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i) e^{[c_M - c(x^T)]k} \xrightarrow{P} 0. \quad (13)$$

Utilizing the relation

$$0 \leq P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i) \leq P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i) e^{[c_M - c(x^T)]k},$$

it can be derived from Eq. (13) that

$$\sum_{x^T \in \bar{X}^T} P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i) \xrightarrow{P} 0.$$

Therefore,

$$\lim_{k \rightarrow \infty} P(x^T = x^{T*} | \mathbf{z}_{1:k}^i) = 1 - \lim_{k \rightarrow \infty} \sum_{x^T \in \bar{X}^T} P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i) = 1.$$

□

B. Proof for moving robots

The difficulty of consistency proof for moving robots lies in the fact that each robot makes observations at multiple positions. Here, the main idea is to classify robot observation positions into two disjoint sets: *infinite-observation spots* that contains positions where a robot makes infinite observations, and *finite-observation spots* that contains positions where the robot makes finite observations. Before stating main theorem, the following lemma is introduced.

Lemma 1. For a set of robots moving within a collection of finite positions, each robot has at least one position where infinite observations are made as k tends to infinity.

Proof. Let $n_j^{i,k}$ denote the times that i^{th} robot visits j^{th} position by time k . Then, $\sum_j n_j^{i,k} = k$. It is straightforward to see that $\exists n_j^{i,k}$, such that $n_j^{i,k} \rightarrow \infty$, as $k \rightarrow \infty$. □

Theorem 2. If robots move within a collection of finite positions, the estimated target position converges to the true position of target in probability using LIFO-DBF, i.e.,

$$\lim_{k \rightarrow \infty} P(x^T = x^{T*} | \mathbf{z}_{1:k}^i) = 1, \quad i = 1, \dots, N$$

Proof. Similar to Theorem 1, the batch form of DBF at k^{th} step is

$$\frac{P_{pdf}^i(x^T | \mathbf{z}_{1:k}^i)}{P_{pdf}^i(x^{T*} | \mathbf{z}_{1:k}^i)} = \frac{P_{pdf}^i(x^T) \prod_{j=1}^N \prod_{l=1}^{k_j^i} P(z_l^j | x^T; x_l^R)}{P_{pdf}^i(x^{T*}) \prod_{j=1}^N \prod_{l=1}^{k_j^i} P(z_l^j | x^{T*}; x_l^R)}. \quad (14)$$

The only difference from Eq. (6) is that $P(z_l^j | x^T; x_l^R)$ in Eq. (14) varies as the robot moves. For each robot, there exists at least one position where infinite observations are made as $k \rightarrow \infty$, according to Lemma 1. All positions can be classified into finite-observation spots and infinite-observation spots. For the former, by referring to Eq. (10) in proof of Theorem 1, it is easy to know that their contribution to Eq. (14) is zero when $k \rightarrow \infty$. Therefore, Eq. (14) can be reduced to only consider infinite-observation spots, which is similar to proof of Theorem 1. □

Remark 5. Consistency implies that all individual PDFs converge to the same distribution (true target PDF), thus the consensus is also guaranteed. It must be noted that traditional statistics dissemination-based methods only ensure consensus of individual PDFs [7], [8]. To the best knowledge of authors, there is no proof of consistency on estimated target position.

V. SIMULATION

This section simulates two scenarios of target localization to demonstrate the effectiveness of LIFO-BDF. In all scenarios, six robots are utilized and each robot is equipped with a binary sensor. All sensors are modeled with identical Gaussian functions [21]:

$$P(z_k^i = 1 | x_k^T; x_k^{R,i}) = e^{-\frac{1}{2}(x_k^T - x_k^{R,i})^T \Sigma^{-1} (x_k^T - x_k^{R,i})} \quad (15a)$$

$$P(z_k^i = 0 | x_k^T; x_k^{R,i}) = 1 - P(z_k^i = 1 | x_k^T; x_k^{R,i}). \quad (15b)$$

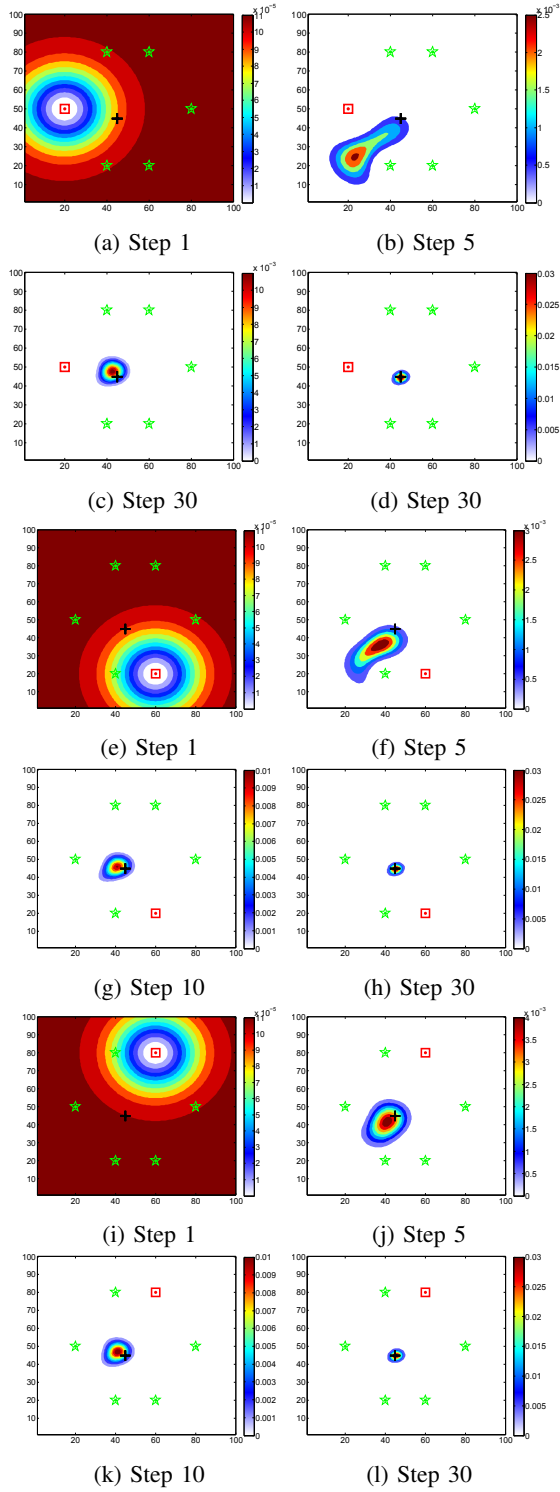


Fig. 4: Individual PDFs at different steps in “static robots + static target” scenario: 1st robot (a)-(d); 3rd robot (e)-(h); 5th robot (i)-(l). Robots are numbered counterclockwise, with the left-most one being the 1st. The square denotes the robot, whose individual PDF is plotted, and stars represent other robots. The cross stands for the target.

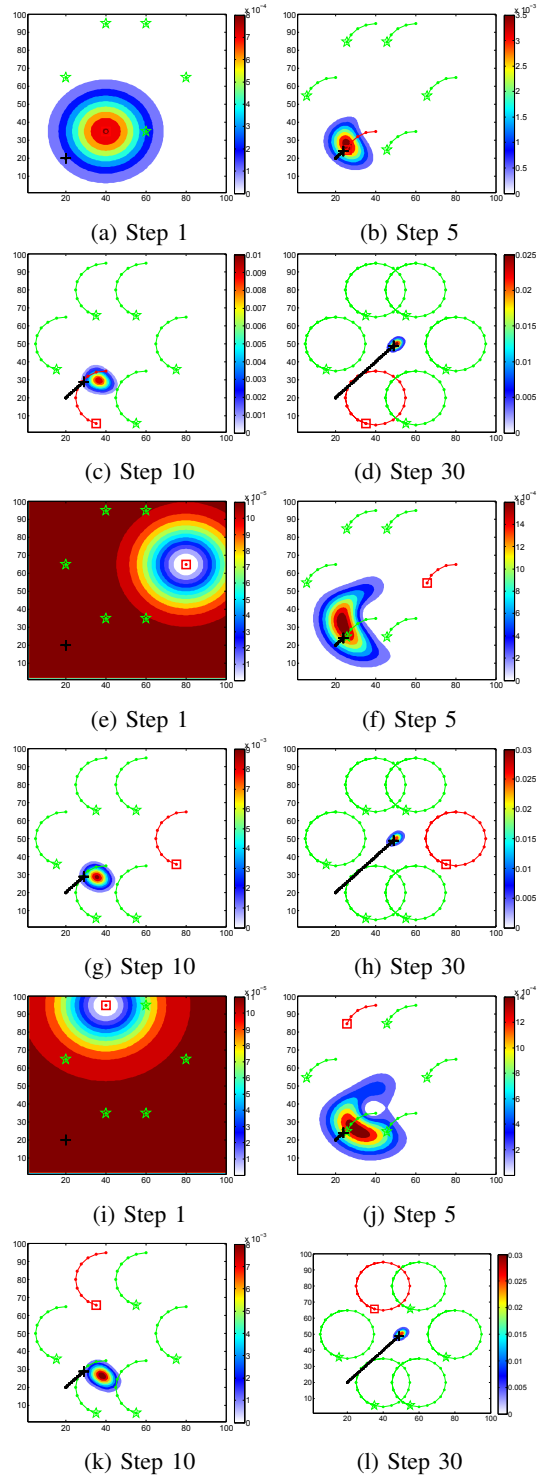


Fig. 5: Individual PDFs at different steps in “moving robots + moving target” scenario: 2nd robot (a)-(d); 4th robot (e)-(h); 6th robot (i)-(l). Robots move in circles shown in red (the robot of focus) and green (other robots). The square and stars denote current positions of robots. The trajectory of the target is represented by the black line.

The first scenario consists of six static robots and a single static target. The second scenario subsequently deals with six moving robots for localizing a moving target. Both robot and target positions are assumed to be manually controllable at each time step.

A. Static Robots, Static Target

The positions of six static robots are shown as stars and square in Fig. 4. The LIFO-DBF for static target is implemented on each robot for target localization. The networked robots use a ring communication topology that each robot can communicate with two fixed neighbors. Fig. 4 shows the estimation results of the static target. After the initial observation, each robot forms a circular individual PDF, centered at its own position. The circular PDF happens because the Gaussian sensor model (Eq. (15)) only depends on the distance between robot and target, not the bearing angle. As more observations are fused, the posterior individual PDF concentrates to the true location of the target, which accords with the consistency of LIFO-DBF. Section V-B shows the decreasing entropy of individual PDFs over time. This confirms the effectiveness of LIFO-DBF in reducing the uncertainty of target position.

B. Moving Robots, Moving Target

In this scenario, the six robots are controlled to move in circular trajectories periodically while the target moves linearly. Readers interested in motion planning of robots for target localization can refer to [27]–[29]. The target dynamics is given by a single-integrator model: $x^T(k+1) = x^T(k) + v\Delta T$, where v is the constant velocity of the target, and ΔT is the sampling time. The LIFO-DBF described in Section III-C is utilized for target localization. Fig. 5 shows the estimation results of the moving target. It is interesting to notice that the posterior individual PDFs concentrate to the true target location even when the target constantly moves. Section V-B shows the decreasing entropy of target PDF over time.

VI. CONCLUSION

This paper presents a measurement dissemination-based distributed Bayesian filtering (DBF) method for a multi-robot network by utilizing the Latest-In-and-Full-Out (LIFO) protocol for observation exchange. Different from statistics dissemination approaches that transmit posterior distributions or likelihood functions, each robot under LIFO only exchanges with neighboring robots a full communication buffer consisting of latest available measurements, which significantly reduces the transmission burden between each pair of robots from the order of environmental size to that of robot number. Under the condition of fixed and undirected topology, LIFO can guarantee non-intermittent dissemination of all observations over the network within finite time via local communication among direct neighborhood. It is worth noting that LIFO is a general measurement exchange protocol and applicable to various sorts of sensors. Two types of LIFO-based DBF algorithms are proposed to estimate individual PDF for static and moving target, respectively. For the static target, each

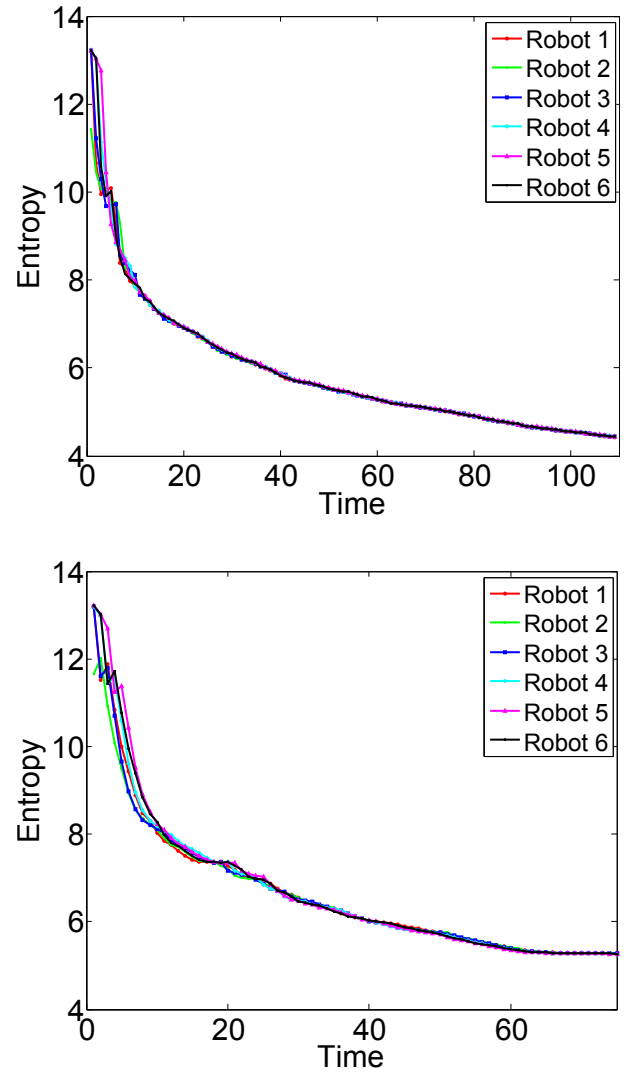


Fig. 6: Top figure: entropy of target PDF using static robots. Bottom figure: entropy of target PDF using moving robots.

robot locally fuses the newly received observations while for the moving target, a record set of historical observations is stored and updated. The consistency of LIFO-based DBF is proved by utilizing the law of large numbers, which ensures that estimated target position converges in probability to the true target position when the number of observations tends to infinity.

Future work includes how to handle other types of sensors and switching topology. Other types of sensors may have biased observations and subject to non-Bernoulli distribution, which complicates the analysis of LIFO-based Bayesian filters. The switching topology, including package loss, can lead to unpredictable delay and intermittent transmission, which may affect the consistency and consensus of LIFO-DBF.

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