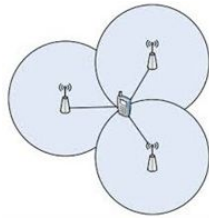


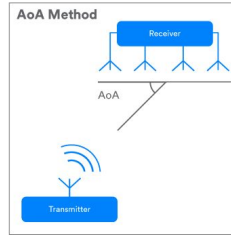
# Localisation Technique

RF-based



## Multi-Lateration

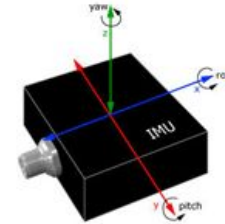
Pseudo-Ranging with  
Received Signal  
Strength Index (RSSI)  
or Round Trip Time  
(RTT)



## Multi-Angulation

Angle of Arrival/  
Angle of departure  
(AoA/AoD) with  
Bluetooth 5.1

IMU-based

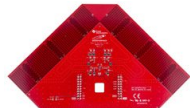


## Pedestrian Dead Reckoning

Gyroscope,  
accelerometer and  
magnetometer

# Comparison of Techniques

PDR	AoA/AoD	RSSI	RTT
<ul style="list-style-type: none"><li>• Very low-cost</li><li>• Independent, low infrastructure support</li></ul>	<ul style="list-style-type: none"><li>• High accuracy</li><li>• <b>0.25 m</b> Mean Absolute Error (MAE), with variance of <b>1.32 m</b> [1]</li></ul>	<ul style="list-style-type: none"><li>• Low-cost</li><li>• Satisfactory accuracy MAE of <b>~3 m</b> with user feedback[2]</li></ul>	<ul style="list-style-type: none"><li>• Low-cost</li><li>• Less vulnerable to environmental factors</li><li>• Potentially higher accuracy than RSSI</li></ul>
<ul style="list-style-type: none"><li>• Cumulative error</li><li>• Knowledge of initial state</li></ul>	<ul style="list-style-type: none"><li>• Incompatibility (Bluetooth 5.1)</li><li>• High cost</li><li>• \$150 array antenna</li></ul>	<ul style="list-style-type: none"><li>• Vulnerable to environmental factors</li><li>• Accuracy can be improved</li></ul>	<ul style="list-style-type: none"><li>• High frequency clock required</li><li>• Uncertainty in node internal processing time</li></ul>

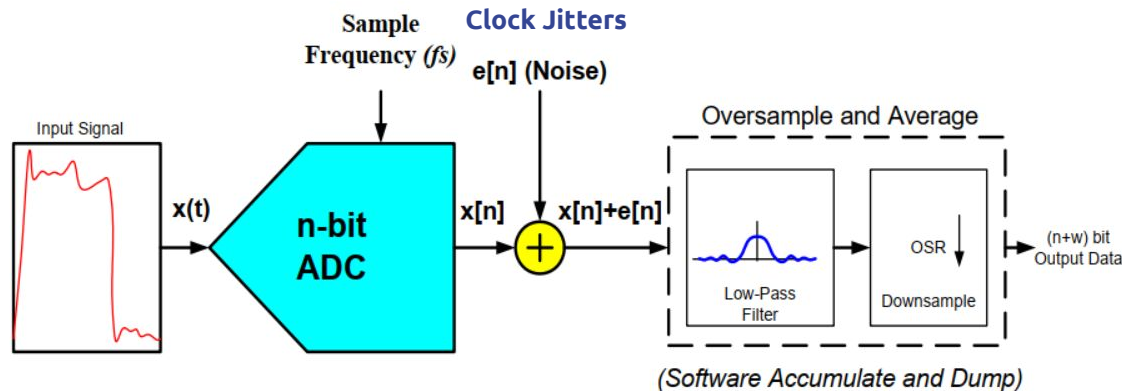


# Oversampling and Averaging

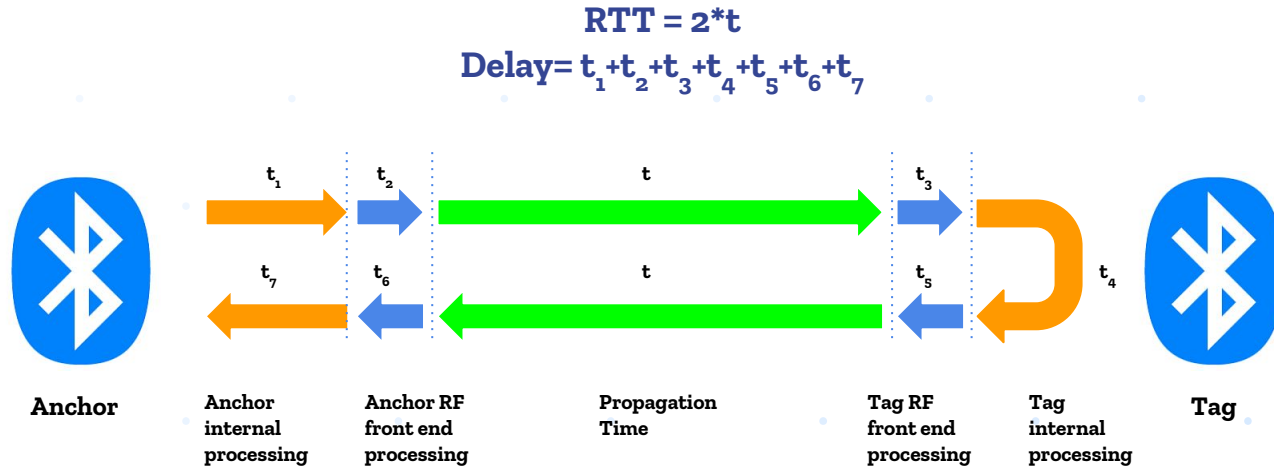
- Increase measurement resolution [3]
- Eliminate the need for expensive ADCs
- Reduce data throughput
- Applicable to system with 'white noise'

$$f_{os} = 4^W \cdot f_s$$

$f_{os}$  : Oversampling frequency  
 $W$ : Additional Bit of resolution  
 $f_s$  : Sampling frequency



# BLE RTT Ranging



## Key Limitations:

- Uncertainty in delay time
- System resolution

# BLE RTT Ranging (Hardware Considerations)



**Anchor Node**  
**nRF52 Series DK**

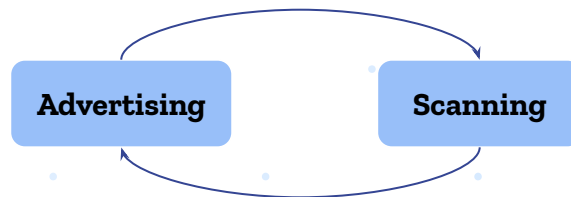
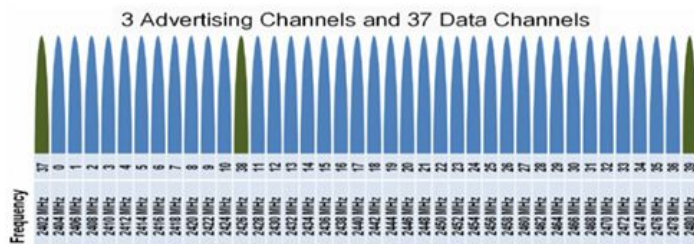
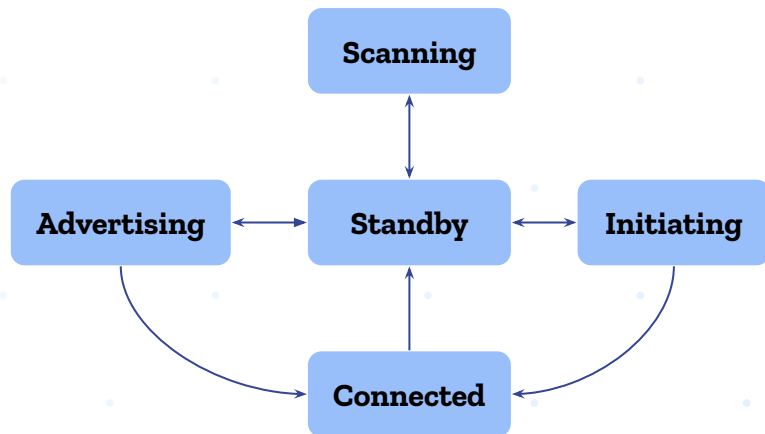
- **RADIO** peripheral to access into bluetooth low level state machine
- 16 MHz **TIMER** peripheral
- Programmable Peripheral Interconnect (**PPI**)



**Tag Node**  
**nRF52840 Dongle**

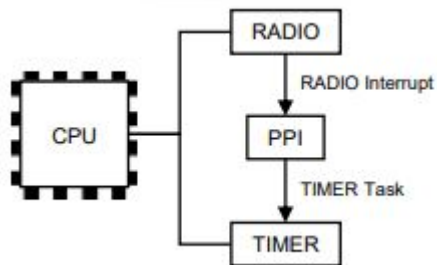
- **Powerful.** Same features as nRF52840 DK
- **Compact.** 46.4 mm \* 15.2 mm

# BLE Link Layer State Machine

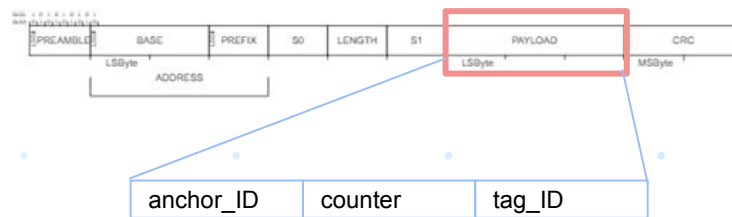


- Measure RTT without pairing
- Reduce processing time
- Increase sampling rate

# Reducing Node Processing Time



**Programmable Peripheral  
Interconnect (PPI)**



**Low Packet Size  
Simple Logic at Tag**

# BLE RTT Ranging (System Resolution)

BLE Packet Propagation Speed:

**3e8 m/s**

TIMER peripheral frequency:

**16 MHz**

ToF resolution

$3e8 / 16e6 = \mathbf{18.75\ m}$

RTT resolution

$(3e10 / 16e6) / 2 = \mathbf{9.375m}$

$$f_{os} = 4^w \cdot f_s$$

Desired System resolution:

**~ 1 m**

Additional Bits:

**$\log_2(9.375/1) = 3.23$**

Oversampling Requirements:

**$4^{3.23} \sim 90\ X$**

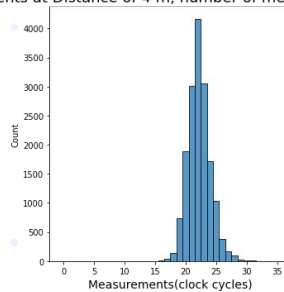


# BLE RTT Ranging (test result)

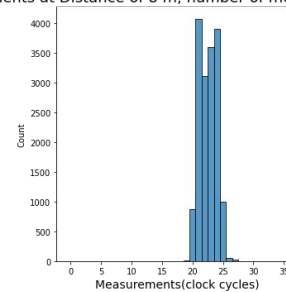


NUS E1 Corridor

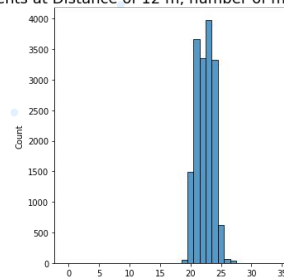
Measurements at Distance of 4 m, number of measurement: 16489



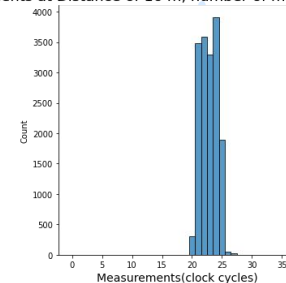
Measurements at Distance of 8 m, number of measurement: 16670



Measurements at Distance of 12 m, number of measurement: 16594



Measurements at Distance of 16 m, number of measurement: 16550

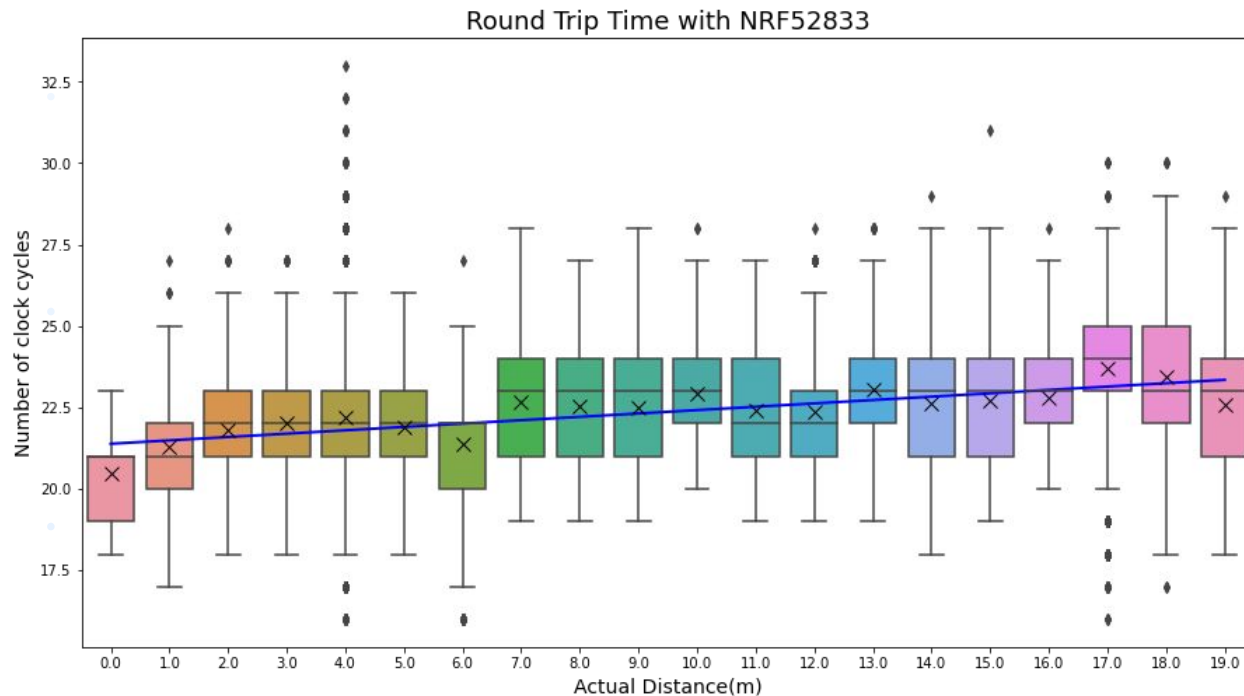


# BLE RTT Ranging (test result)

$$t = 0.1032 \cdot d - 21.386$$

d : actual distance

t : clock cycle measured





# Results

# 5

# Results



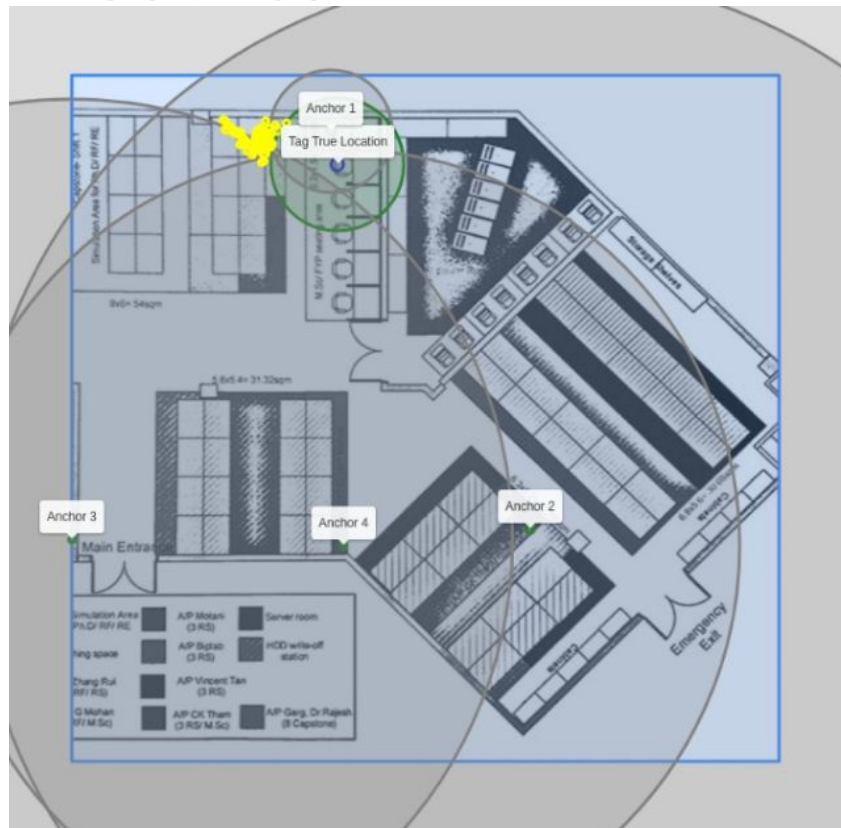
	x	y
truth	6	8
mean	6.451	8.162
var	0.167	1.138
mae	0.479	

# Results



	x	y
truth	10	7.5
mean	9.242	8.479
var	0.132	0.737
mae	1.238	

# Results



	<b>x</b>	<b>y</b>
<b>truth</b>	8	18
<b>mean</b>	5.509	18.797
<b>var</b>	0.201	0.101
<b>mae</b>	2.615	

# Results

