

Channel Tracking and Prediction with Deep Temporal Convolutional Networks

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Abstract—This paper proposes a temporal convolutional network (TCN)-based neural structure for channel tracking and prediction and compares the performance of the Kalman filter (KF) and TCN in three settings: (i) a simulated setting where the channel obeys a linear autoregressive (AR) model with additive white Gaussian noise where the Kalman filter is known to be optimal, (ii) a simulated setting where the ideal assumptions required for Kalman filter optimality are not satisfied due to the mismatch between the presumed linear time-varying AR model and the true model and (iii), a simulated setting where the AR channel follows the Gilbert-Elliott model with good and bad states. We also compare our results in the three scenarios with a least squares approach and the Ricatti equation which provides the asymptotic limits. Numerical mean squared error (MSE) results are presented to demonstrate the accuracy achieved by the machine learning approach and the loss of performance experienced by the KF as a function of the amount of model mismatch. The results demonstrate that the machine learning approach achieves performance close to optimal irrespective of the amount of model mismatch.

classical Kalman filter (KF) is the optimal estimator and predictor [cite](#). In non-ideal situations, like for example, when the underlying dynamical model does not match the dynamics of the actual channel, the KF is no longer optimal.

We propose a better solution using advances in deep learning, specifically using sequence prediction algorithms in the task of channel tracking and prediction. While recurrent neural networks (RNNs) and long short-term memory (LSTM) have historically been the most popular choice for sequence prediction – and, indeed, prior work has demonstrated promising results for their use in channel tracking [2] [3] – recent results in machine learning have shown that a new architecture called temporal convolutional networks (TCNs) can often outperform LSTM-based RNNs in sequence prediction problems [4]. In addition to their performance advantage in a wide range of sequence prediction problems, TCNs have a number of implementation advantages over RNNs in that they admit a more parallelizable implementation and have reduced memory requirement for training. TCNs also have several structural advantages including an adjustable receptive field size and avoidance of the problem of exploding/vanishing gradients known to plague RNNs.

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1. INTRODUCTION

Channel tracking and prediction are critical tasks in communication systems with mobility. The ability to accurately track and predict channels is necessary to enable many aspects of modern communication systems including coherent demodulation, rate and power control, and beamforming [1].

Under an ideal AR channel model with linear dynamics, Gaussian noise and known noise covariance matrices, the

2. CHANNEL MODEL

There are many different channel models, one of the most common being the Gauss-Markov channel model, otherwise known as the auto-regressive (AR) model. Due to the inherent Gaussian nature of the noise present in the space and air we are surrounded by as well as the causal state dependency on current states of the transmission medium from previous states, it makes sense to assume that the channel can be modeled this way. This is exactly what an AR process is, and previous bodies of work have supplied the motivation and justification for us to choose this model [1] [5].

In general, a noisy observation $z[k]$ of an N th order autoregressive (AR) process $x[k]$ is described by the equations

$$\begin{aligned}x[k] &= \left(\sum_{n=1}^N f_n x[k-n] \right) + v[k] \\ z[k] &= x[k] + w[k]\end{aligned}$$

where $v[k]$ and $w[k]$ are both Gaussian, zero-mean noise with variances σ_v^2 and σ_w^2 , assumed to be uncorrelated.

Throughout this paper, we constrain the process order to be AR-2 where the process (or state) $x[k]$ and noisy observation $z[k]$ are given by

$$\begin{aligned} x[k] &= f_1 x[k-1] + f_2 x[k-2] + v[k] \\ z[k] &= x[k] + w[k] \end{aligned}$$

In state-space form, this becomes:

$$\begin{aligned} \mathbf{x}[k] &= \mathbf{F} \mathbf{x}[k-1] + \mathbf{v}[k] \\ z[k] &= \mathbf{H} \mathbf{x}[k] + w[k] \end{aligned}$$

where

$$\begin{aligned} \mathbf{x}[k] &= \begin{bmatrix} x[k] \\ x[k-1] \end{bmatrix} \\ \mathbf{v}[k] &= \begin{bmatrix} v[k] \\ 0 \end{bmatrix} \\ \mathbf{F} &= \begin{bmatrix} f_1 & f_2 \\ 1 & 0 \end{bmatrix} \\ \mathbf{H} &= [1 \quad 0] \end{aligned}$$

The AR process states are complex numbers which contain information about the phase and gain modulation inherent to the channel itself. Under the assumption that the transmission frequency band is very narrow in spectrum, we can model the channel as a singular complex number which alters both the phase and magnitude of signals passed through it. We use a neural network to extract the nonlinear and weighted relationships between samples such that we can make better predictions and estimations of the state than we could otherwise with linear estimators like the least squares and Kalman filter approaches.

3. DATA GENERATION

We designed a data generation script which will output m AR process sequences of length n . This data is used for training and testing the least squares (LS), Kalman filter (KF) and TCN state prediction and estimation systems. Separate training and testing subsets of data are created to ensure validity in the numerical results for the non-mismatched and mismatched AR parameter cases as well as the Gilbert-Elliott case.

The format of the data that is generated is as follows:

$$AR = \begin{bmatrix} P_{10} & P_{11} & \dots & P_{1n} \\ P_{20} & P_{21} & \dots & P_{2n} \\ \vdots & & \ddots & \\ P_{m0} & P_{m1} & \dots & P_{mn} \end{bmatrix}$$

Where the first index for each element corresponds to the process ID and the second index is the sample number in that specific AR process.

Case 1: Static AR Processes

Case 2: Varied AR Processes

Case 3: Gilbert-Elliott Model

4. LINEAR ESTIMATORS

The most common approaches to accurately tracking the channel described in Section 2 use linear estimators such as the least squares solution or the Kalman filter. The LS solution is the most straightforward of the two and simply tries to find a line of best fit to the training data which is then used in further evaluations for test data. The KF on the other hand requires knowledge of the channel statistics such that a probabilistic estimation and prediction can be made of the current and next states.

Riccati Equation

The Riccati equation allows us to have a lower bound for the best possible performance in channel estimation we could possibly have with a model mismatch, assuming access to an infinite dataset. In this specific case, this equation will always converge to a lower MSE than any other channel estimation method we are using (LS, KF, TCN). In the matched model case, the Riccati will simply verify that the KF is working properly, as they both converge to and provide the same solution. The Riccati in the discrete time domain is implemented with the following equation:

$$X = A^T X F - (F^T X H)(R + H^T X H)^{-1}(H^T X F) + Q$$

Least Squares

The least squares solution is perhaps the simplest and most straight-forward approach to channel tracking. Using this methodology, we obtained least squares filter coefficients which transform the measured state matrix (Z) into the best prediction or estimation (\hat{x}) that we can make given a sequence history of N and a filter order of M . The prediction/estimation and least squares coefficient solutions (a_{ls}, b_{ls}) are given by the following equations:

$$\begin{aligned} \hat{x}_{est} &= Z a_{ls} \\ \hat{x}_{pred} &= Z b_{ls} \\ a_{ls} &= (Z^T Z)^{-1} Z^T x_{est} \\ b_{ls} &= (Z^T Z)^{-1} Z^T x_{pred} \\ x &= [x[k] \dots x[k-M]]^T \\ \hat{x}_{pred} &= [\hat{x}[k-1] \dots \hat{x}[k-M-1]]^T \\ \hat{x}_{est} &= [\hat{x}[k] \quad \hat{x}[k-1] \quad \dots \quad \hat{x}[k-M]]^T \\ a_{ls} &= [a_0 \quad a_1 \quad \dots \quad a_N]^T \\ b_{ls} &= [b_0 \quad b_1 \quad \dots \quad b_N]^T \end{aligned} \quad (1)$$

$$Z = \begin{bmatrix} z[k-1] & \dots & z[k-N-1] \\ z[k-2] & \dots & z[k-N-2] \\ \vdots & \ddots & \\ z[k-M-1] & \dots & z[k-M-N-1] \end{bmatrix}$$

The least squares filter coefficients are computed once using a training data sequence consisting of many segments of either

one AR process or many, depending on the model being used. Both the mismatched and matched model cases are evaluated, with training occurring on large collections of AR processes and testing on individual, longer sequences.

Kalman Filter

Given knowledge of the channel parameters and statistics via data collection, we can implement the Kalman filter approach to channel tracking. We wish to estimate the current state as well as predict the future state of the AR process. To realize the KF in this situation, we used the following state update equations:

$$\begin{aligned}\hat{x}[n|n-1] &= \mathbf{F}\hat{x}[n-1|n-1] \\ \mathbf{M}[n|n-1] &= \mathbf{F}\mathbf{M}[n-1|n-1]\mathbf{F}^T + \mathbf{Q} \\ \mathbf{K}[n] &= \frac{\mathbf{M}[n|n-1]\mathbf{H}}{\sigma_w^2 + \mathbf{H}^T\mathbf{M}[n|n-1]\mathbf{H}} \\ \hat{x}[n|n] &= \hat{x}[n|n-1] + \mathbf{K}[n](z[n] - \mathbf{H}^T\hat{x}[n|n-1]) \\ \mathbf{M}[n|n] &= (\mathbf{I} - \mathbf{K}[n]\mathbf{H}^T)\mathbf{M}[n|n-1]\end{aligned}$$

Notation	Description
$\hat{x}[n n-1]$	State prediction
$\hat{x}[n-1 n-1]$	Correction value
$\mathbf{M}[n n-1]$	Minimum prediction MSE
$\mathbf{M}[n-1 n-1]$	Minimum estimation MSE
\mathbf{Q}	Process noise
$\mathbf{K}[n]$	Kalman gain
σ_w^2	Measurement noise covariance

Generally, if the Kalman filter has perfect knowledge of the real AR coefficients, the MSE of this system will approach the Riccati equation MMSE with longer datasets corresponding to closer matching between the two values. In our case, we tested both circumstances; when the Kalman filter has perfect knowledge of the coefficients and also when there is a slight deviation.

5. TEMPORAL CONVOLUTIONAL NETWORK

The temporal convolutional network (TCN) is the neural network architecture we chose to design and test against the least squares and Kalman filter solutions. The TCN has proven to be more successful in sequence identification problems than recurrent neural networks (RNN) and long-short term memory neural networks (LSTM). The structure and general design of this neural network was previously created by another research team [4] which we used and altered for channel estimation specific inputs and outputs.

The TCN structure is essentially a one dimensional, fully connected network with causal convolutions. The main differences between a traditional convolutional neural network and

the TCN are the diluted causal convolutions between network layers and the ability to specify a desired output sequence length. To accomplish this, the network contains hidden layers which are all of the same length and uses zero padding to keep the dilutions feasible and maintain the output size specification. Convolution dilution happens in this network to increase the receptive field of each convolutional layer, providing the network the ability to account for sequence elements that are further back in the input history.

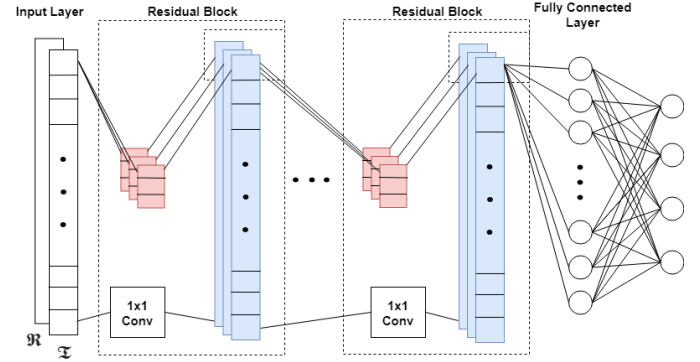


Figure 1. Temporal Convolutional Network Architecture

The TCN consists of multiple "residual blocks" which act as fundamental construction elements in this architecture. One instance of this network may consist of many residual blocks, all daisy-chaining in one long sequence. These residual blocks consist of two layers of diluted, causal convolutions and a non-linearity (ReLU) on the output of each layer. The residual blocks contain an identity mapping which aids in training for slight variations around the input sequence by explicitly weighting the output with a scaled version of the input before any convolutions took place.

Due to the complex nature of the channel values and lack of PyTorch support for complex valued neural networks, the imaginary and real components had to be split into separate floating point numbers in order to effectively train the network. This splitting into real and imaginary components has already been done by previous research teams with favorable results [6]. The loss function for this network is the mean-squared error (MSE), and for complex values this is calculated in the following way:

$$MSE = E(|x - \hat{x}|^2)$$

Where x and \hat{x} are both complex valued states (actual and computed states, respectively).

6. RESULTS

Case 1: Static AR Processes

	MMSE	Least Squares	Kalman	TCN
Estimation	ay	doe	ay	doe
Prediction	aye	doe	ayez	doez

Case 2: Varied AR Processes

	MMSE	Least Squares	Kalman	TCN
Estimation	ay	doe	ay	doe
Prediction	aye	doe	ayez	doez

Case 3: Gilbert-Elliott Model

	MMSE	Least Squares	Kalman	TCN
Estimation	ay	doe	ay	doe
Prediction	aye	doe	ayez	doez

7. CONCLUSION

This is the conclusion.

All source code for this experiment is available at —
<https://github.com/aspectlab/deepchannel>

ACKNOWLEDGMENTS

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BIOGRAPHY



Arick Grootveld is currently pursuing a B.S. in electrical engineering from WWU and expects to graduate in June 2020. His current research activities include... Lorem ipsum dolor sit amet, consectetur adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetur id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo. Cras viverra metus rhoncus sem. Nulla et lectus vestibulum urna fringilla ultrices. Phasellus eu tellus sit amet tortor gravida placerat. Integer sapien est, iaculis in, pretium quis, viverra ac, nunc. Praesent eget sem vel leo ultrices bibendum. Aenean faucibus. Morbi dolor nulla, malesuada eu, pulvinar at, mollis ac, nulla. Curabitur auctor semper nulla. Donec varius orci eget risus. Duis nibh mi, congue eu, accumsan eleifend, sagittis quis, diam. Duis eget orci sit amet orci dignissim rutrum.



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