

## Goal of the assignment

The goal of this assignment is to understand how UWB radar works, how to use the radar data collected from an array for indoor localization.

## Data Collection

**Localization of walking in different patterns:** We have collected data from a few participants where the participants followed different paths in the room. These paths include U-shaped path, L-shaped path, 4-shaped path etc.

You can download the data from the following link:

<https://drive.google.com/drive/folders/1oOtnOtpwrlIjq6zgtCnr6Kj95XoOtdzd>

Please note that we are not providing any code for this assignment. Only data! You can implement your algorithms either in Matlab or Python.

## Step-wise Localization

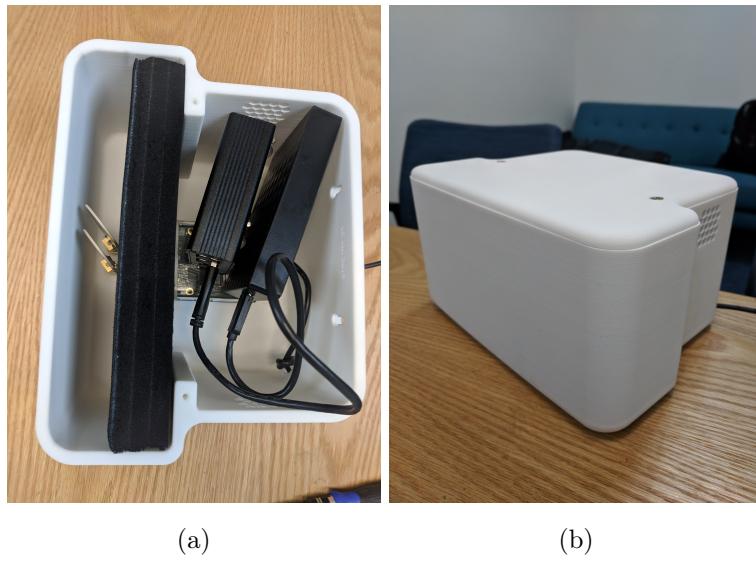


Figure 1: The UWB radar units used for this data collection.

For the data collection we used three Ultra Wide Band (UWB) radar units called PulsON® 440 (P440) Monostatic Radar Module (MRM). Each sensor has a UWB transmitter and a UWB receiver. The transmitter and receiver operating band are generally, 3.1 to 4.8 GHz and the center frequency is 4.3 GHz. The three radars use separate code channels to avoid interference with each other. UWB radar repetitively transmits short duration electromagnetic impulses having extremely low power and very large bandwidth. These impulses fall upon both stationary and moving objects and the reflected pulses travel back to the receiver antenna of the UWB radar. The raw reflected pulses go through some signal processing steps to convert to the baseband signal which preserves time-of-flight (ToF) information from different objects/reflectors available in the environment. The range/distance between

the radar and different objects can be calculated from the time of flight by multiplying it with the speed of Light (EM wave). In order to estimate the ToF between radar and a user, we apply different signal processing algorithms including static clutter removal (to remove the ToF information from inert objects in the raw baseband signal), band-pass filtering and envelope detection. Figure 2 shows the raw UWB radar data, clutter removed data and the envelope of the clutter removed data. The x-axis corresponds to fast time or range (meter) while the y-axis corresponds to slow time or scan number. A scan refers to the backscattered/reflected signal captured after an impulse signal is transmitted to an environment. This type of range vs scan number plots are typically referred as water fall plots. For the localization part of this assignment, we have provided you with the clutter removed, envelope detected 2 dimensional array signal.

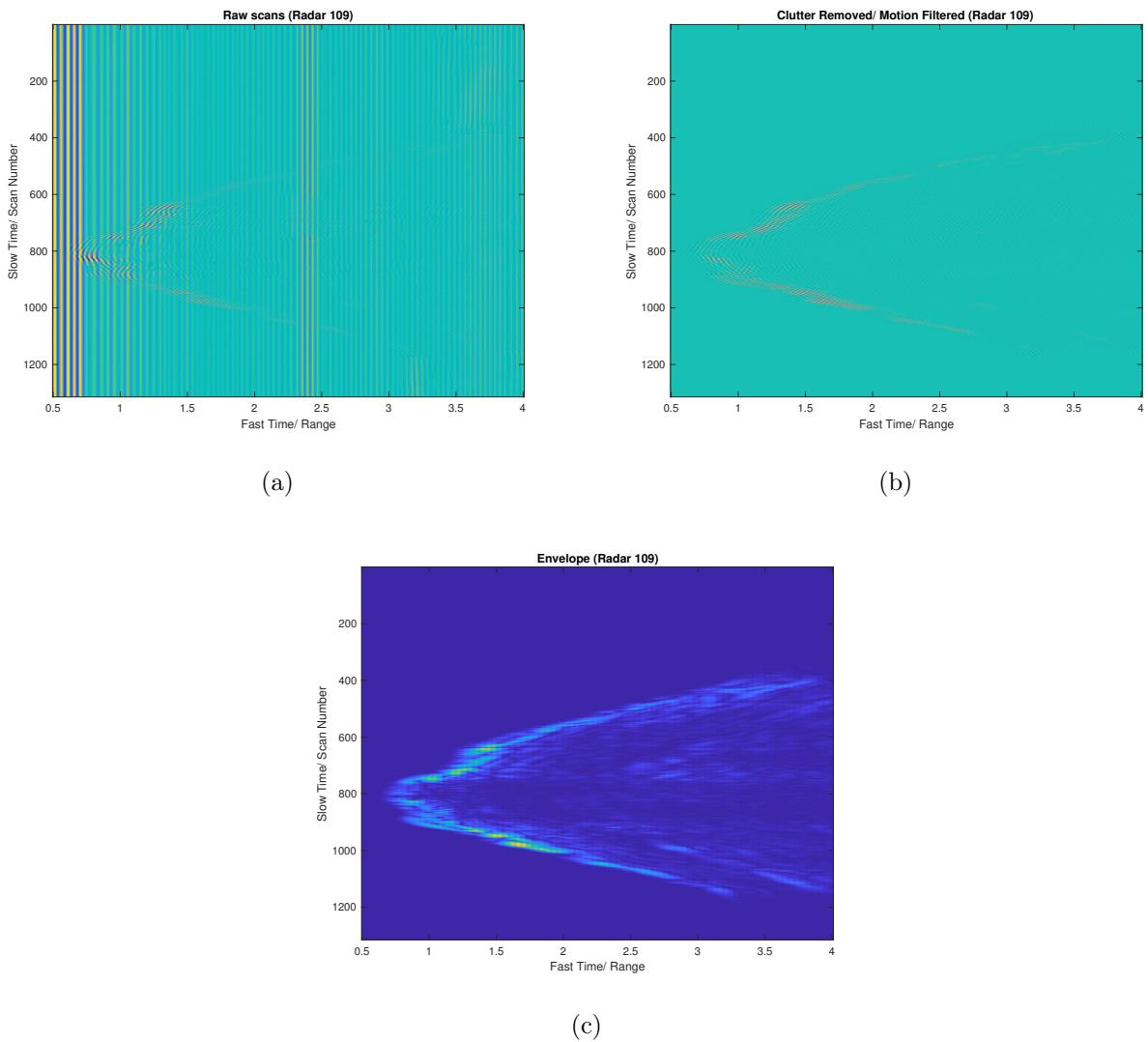


Figure 2: illustrates (a) the raw UWB radar data, (b) the clutter removed radar data and (c) the envelop of the clutter removed radar data in 3 different water fall plots. The range vs scan number plots are typically referred as water fall plots.

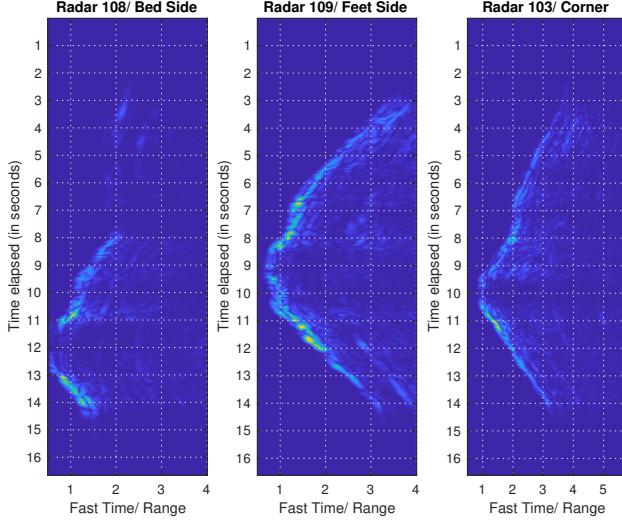


Figure 3: shows the waterfall plots of three time synchronized radar data.

### Thresholding:

After detecting the envelope of the clutter removed signal, we can easily observe the presence of human body motion in the waterfall graph. By plotting a 3D plot of the envelope detected signal we can decide a threshold value for tracking the moving individual over time. A typical threshold value for the localization dataset and room map is above  $5 * 10^4$ . In a given time instant (or scan), the earliest range bins (i.e., the smallest distance between the radar and the human body) at which the signal strength is greater than the threshold determines the radial distance of the individual from the corresponding radar. UWB impulse radar (IR) can only provide range information based on time-of-flight (ToF) of the received pulses. That is why localization in a 2D plane via UWB-IR requires more than one radar.

### Time Synchronization:

To localize and track a moving person in a room, we need to synchronize consecutive observations of the target individual with its location. Therefore time synchronization of all three radar's observations is crucial. Using the provided Unix timestamps from each radar one can synchronize the envelope detected signals from all the three radars before applying any localization techniques. A time-synchronized envelope detected plot is shown in Figure 3.

### Trilateration:

Trilateration uses only the distance measurements to localize the target. After getting the synchronized consecutive observations of the three radars, the target range bins are obtained through thresholding. Now, one can draw circles using this range as radius and the corresponding radar position as the center like shown in Figure 4.

The intersection of these circles will provide the estimated location of the target in a 2D plane. However, it is expected to have multiple circles drawn for one radar for a particular window due to multiple range bins (human target cannot be considered as a single point). The Time\_Window size

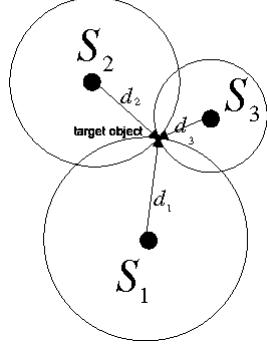


Figure 4: illustrates the trilateration process with the time synchronized radar data from 3 UWB radar units.

is taken 0.25 seconds and Time\_Window\_Shift size is taken 0.125 seconds. There might be several intersection points for a single target for each window as multiple range bins might be selected by the thresholding for a certain window for each Radar. To estimate the position of the target (i.e., the location of the body), we will estimate the geometric centroid of the cluster.

After localization and tracking the 2D plane looks like the following figure which was obtained from walking in pattern "U". For this assignment kalman filtering is not in scope for this assignment, so you will not have to worry about the smoothed blue lines.

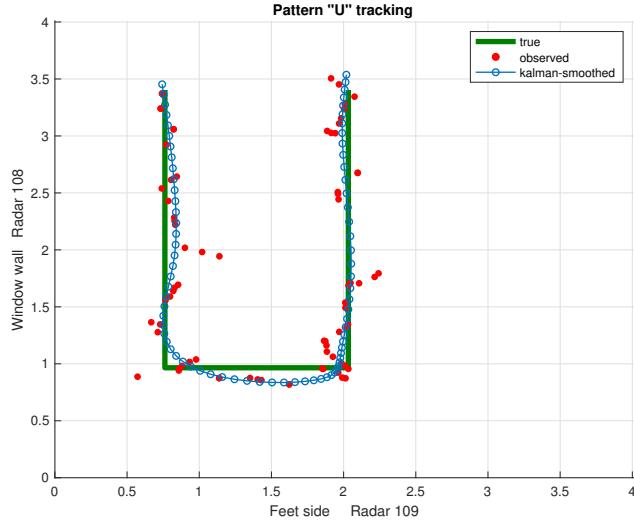


Figure 5: illustrates the localization and tracking on a 2D plane. Each red dot represent the geometric centroid of the clusters. The blue dotted line is estimated with the help of a kalman filter. For this assignment kalman filtering is not in scope for this assignment, so you will not have to worry about the smoothed blue lines.

### **Shadow/ Mirror Location Fallacy:**

In case of localization using only two radars in adjacent walls, shadow/mirror points might appear. This is due to the fact that two circle intersect twice in two different location. This mirror point does

not appear in case of three radars. The mirror location can easily be avoided incorporating the room measurements (the intersection falling outside of the room dimension should be discarded). If two intersections is still available (which might occur in case of short radii) then the intersection closest to the previous observed location should be selected discarding the other one.

## Data Organization

**Localization Dataset:** The localization data set can be found in the folder with the same name. It consists of two participants' walking data. Each participant has data from three radars namely '108', '109' and '103'. In each radar there are files for each walking pattern such as 'diag', 'U', 'gamma', 'L' and 'four'. Also there are three mat files provided in each walking pattern.

- The 'envNoClutterscans.mat' gives the clutter removed envelope detected version of radar scans which is also 2 dimensional matrix like before, where the rows correspond to the 'Slow Time/Scan Number' and columns correspond to the 'Fast Time/Range' as seen in the figure (c). Therefore the value in  $i^{\text{th}}$  row and  $j^{\text{th}}$  column represents the magnitude of envelope detected scans at  $j^{\text{th}}$  range bin from the radar in the  $i^{\text{th}}$  scan.
- The 'range\_bins.mat' and 'T\_stmp.mat' are same as before.

The location of the radars and the walking patterns in room map are shown in Figure 6.

## Data Analysis and Interpretation

- **Step 1 (10 Points):** Visualize the waterfall plots of any one specific patterned walk activity for data from at least two radars. Since at least two radar is needed for localizing the user in 2D space. Please put the figures on a word doc and explain what you are observing. Are there differences in the radar data between different radar sensors?

Hint: It should look like Figure 2c.

- **Step 2 (80 Points):** Perform localization in the localization data-set for both participants and all the patterns using trilateration method. Scatter plot the obtained location points in a 2D graph along with the ground truth patterns. It should look like Figure 5 except the kalman filtered part (Kalman filtering remains outside of the scope of our assignment). Hint: At first try localizing with only two radars e.g. with R108 and R109. It's optional but you can try to use all three radar data for localization for improved localization performance.

## Deliverables

- a report document, where you will put various plots and tables along with your interpretation of these results (in the plots and tables)
- all of your code. Please attach your full code. Please provide us with further information and documentation so that we can easily run your code. Try to comment your code for better readability.

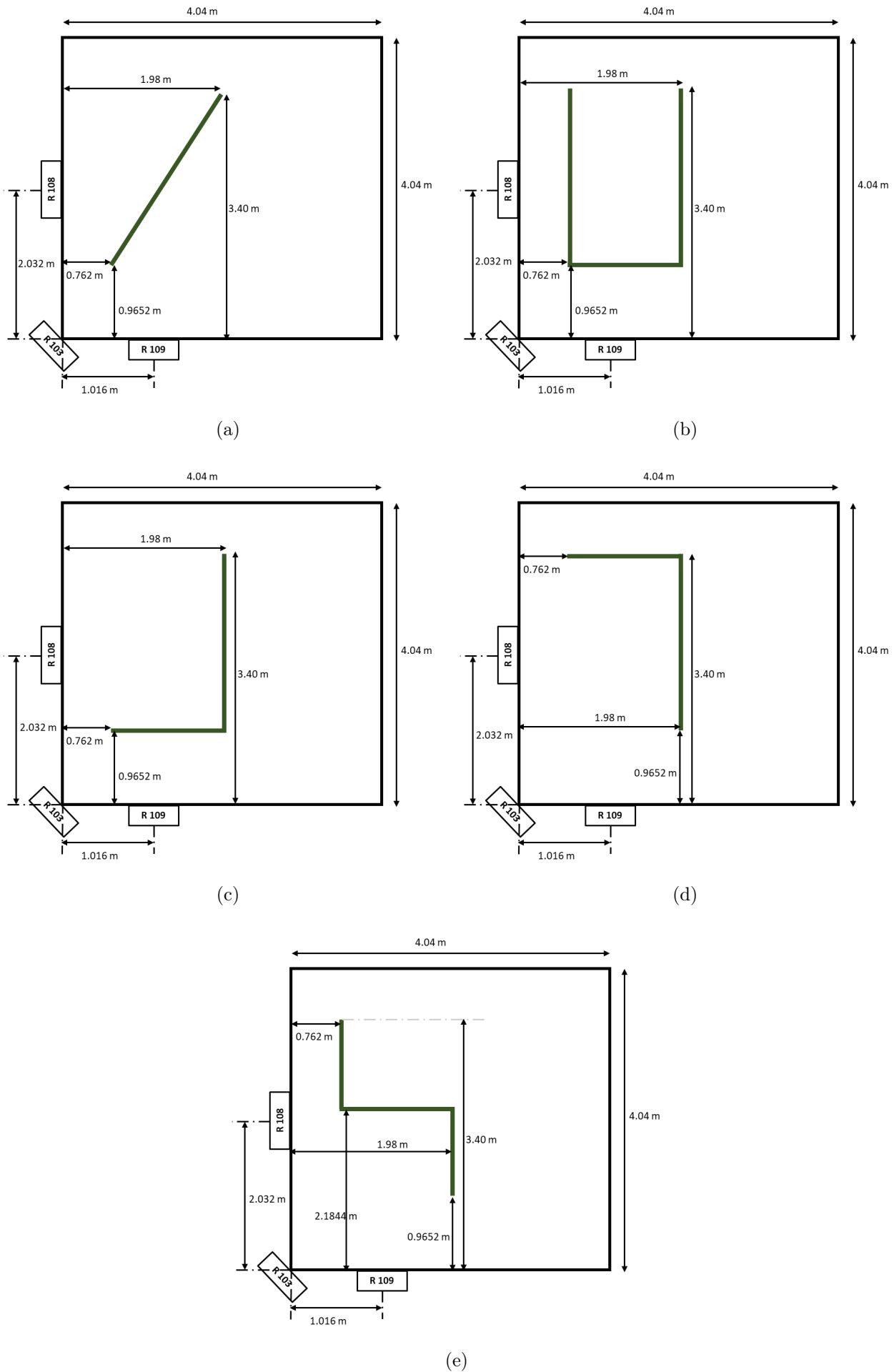


Figure 6: illustrates Room maps for walking in pattern (a) diag (b) U (c) gamma (d)L (e)four