A GRAPH THEORETIC APPROACH FOR MAXIMIZING TARGET COVERAGE USING MINIMUM DIRECTIONAL SENSORS IN RANDOMLY DEPLOYED WIRELESS SENSOR NETWORKS

Sakshar Chakravarty (1305002)
Laboni Sarker (1305115)

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Supervised By
Dr. A K M Ashikur Rahman
Professor, CSE, BUET

INTRODUCTION

- A system consisting of wireless sensors and targets.
- Both deployed randomly.

2 types of sensors:

- Isotropic
  Circular coverage
- Directional (within the scope of this thesis)
  Coverage in a particular direction
  example: camera

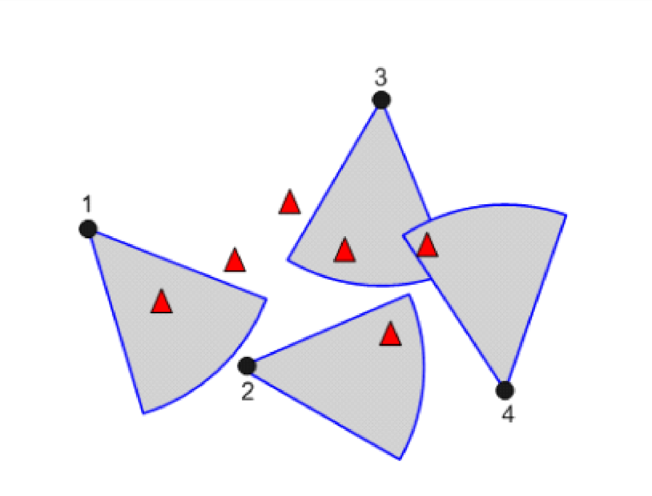
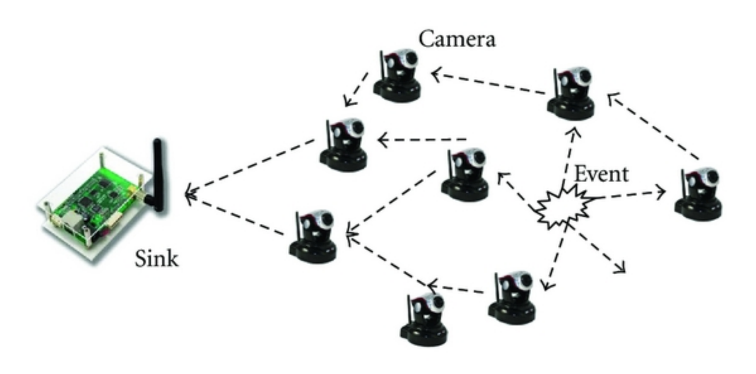


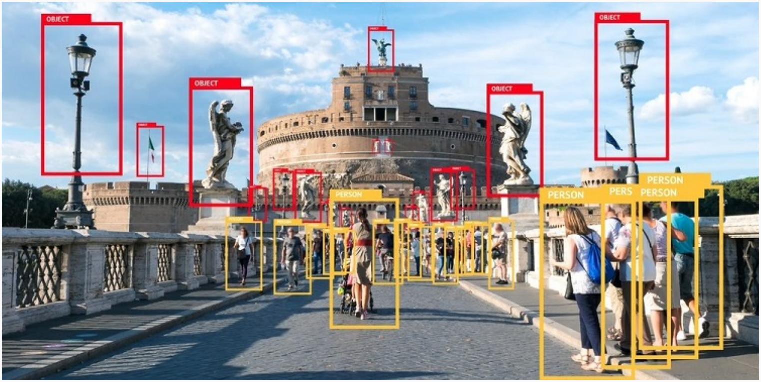
Figure: A random deployment scenario

APPLICATIONS

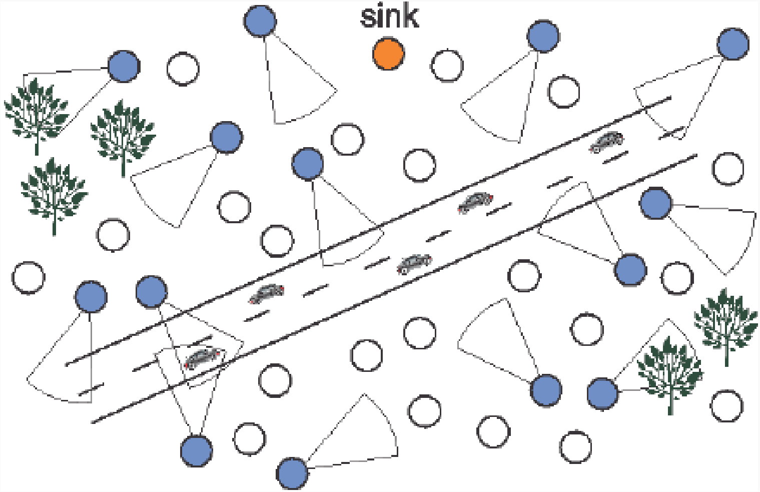
APPLICATION: SURVEILLANCE



APPLICATION: OBJECT TRACKING



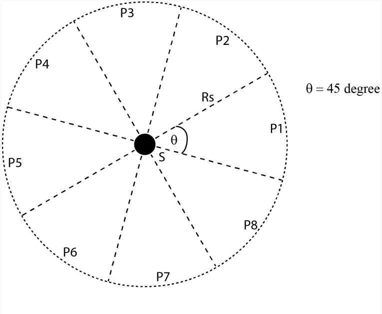
APPLICATION: ENVIRONMENTAL MONITORING



BACKGROUND

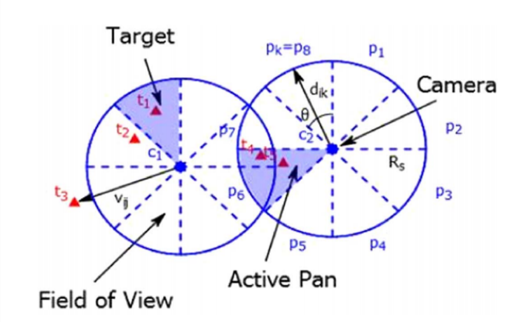
- FOV(Field of View):
  It is the sensing region of a sensor/extent of sensing region which can be captured at any direction.
- Used sensors:
  Pan-tilt-zoom cameras
- Our assumptions:
  Pan-only Cameras

- Parameters:
  - Range (R_s)
  - Angle (θ)



- Assumptions:
  We will consider homogeneous cameras (the parameters will be same for all cameras).

- **TIS test:** This means target in sector (pan) test.



- **Formula:** $\phi_{ij} = \cos^{-1}\left(\frac{\vec{d_{ij}}.\vec{v_{ij}}}{|\vec{d_{ij}}||\vec{v_{ij}}|}\right)$

  i $\phi_{ij} \leq \frac{\theta}{2}$
  ii $|\vec{v_{ij}}| \leq R_s$

- 2 classes of deployment on the basis of the ratio between the number of directional sensors and targets:
  - i **Under Provisioned System:**
    No point of minimization of active sensors.
  - ii **Over Provisioned System (within the scope of this thesis)**
    Minimization of active sensors is an important aspect.

PROBLEM FORMULATION

- Maximization of target coverage
- Minimization of active sensors

- It is an NP-hard problem.
- Formulate different heuristics to achieve a near optimal solution better than the existing one's.

LITERATURE REVIEW

LITERATURE REVIEW

Work	Principle	Description	Comments
Ai and Abouzeid 2006	• Sensor-oriented • Greedy Heuristic	• Integer Linear Programming (ILP) • Centralized Greedy Algorithm (CGA) • Distributed Greedy Algorithm (DGA)	• Poor performance in over-provisioned system • ILP is not scalable to solve large scale scenario • CGA and DGA fail to resolve tie between sensors

LITERATURE REVIEW

Work	Principle	Description	Comments
Munishwar and Abu-Ghazaleh 2013	• Sensor-oriented • Modified Greedy Heuristic	• Centralized Force-directed Algorithm (CFA): Priority is given to the sensors covering targets in a single pan.	• Poor performance in over-provisioned system • Fails to minimize the number of active sensors

LITERATURE REVIEW

Work	Principle	Description	Comments
Munishwar et al. 2011	• Sensor-oriented • Communication between sensors	• Distributed Force-directed Algorithm (DFA): • Each sensor assigns a unique priority • Area based or target based approach • Each sensor orients itself towards maximal coverage pan. • This orientation information exchanged among sensors. • If overlapping coverage found, higher priority sensor prevails.	• Fails to minimize the number of active sensors

LITERATURE REVIEW

Work	Principle	Description	Comments
H. Zannat et al. 2016	• Target-oriented	• Greedy Target Oriented Heuristic (GTOH) • Pure Target Oriented Heuristic (PTOH) • Hybrid Target Oriented Heuristic (HTOH)	• Fails to minimize the number of active sensors.

Work	Principle	Description	Comments
Fusco and Gupta 2009	• k-coverage problem	• Centralized Greedy Algorithm: Assumption: Each sensor has overlapping pans instead of discrete pans.	• Huge variation among targets in achieving the desired k-coverage.
	• Some approximation algorithms related to directional sensors	• orient all the given sensors in order to maximize coverage • place and orient a minimum number of sensors in order to cover the given area • place and orient the given number of sensors to maximize the area covered	

Work	Principle	Description	Comments
Malek et al. 2016	• Balanced k-coverage problem	• Improved the k-coverage solution proposed by Fusco and Gupta (2009) to achieve balanced k-coverage.	• Reduced the number of uncovered targets as well as providing k-coverage to targets as much as possible

- All the heuristics are formulated based on greedy approach.
- Either sensor-oriented or target-oriented.
- In all the works, selection of a sensor and fixing its orientation are merged into a single step.
- Most of them fail to achieve active sensor minimization, only focusing on coverage maximization.
- k-coverage problems address fault tolerance issue, we limit ourselves only to 1-coverage.

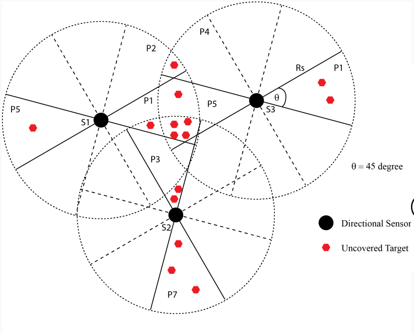
PROPOSED CONTRIBUTIONS

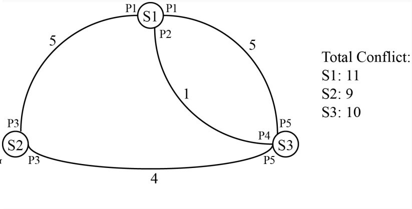
- Fusing both Sensor-oriented Target-oriented approach.
- Splitting the step of selection of sensor and orientation
- Model the problem in graph theoretic approach.

WORK PLAN

- **Nodes:** Sensors (Cameras).
- **Edges**
  Conflict of targets .

EXAMPLE





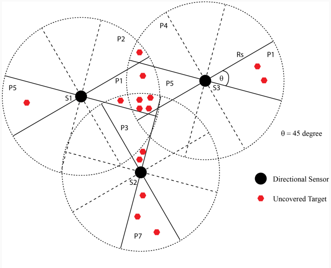
Model a weighted multi-graph.
We can define it as conflict graph.

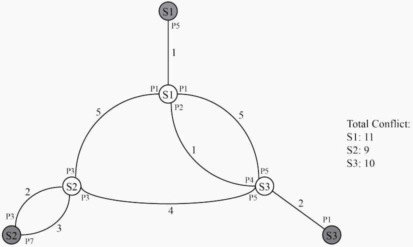
- Different heuristics
  - Total maximum conflicts of the nodes
  - Total minimum conflicts of the nodes

ORIENTATION OF THE SELECTED SENSOR

- Greedy approach
  - That orientation which will cover the total maximum number of targets
- We can also choose the orientation with the maximum/minimum conflict

- **Shadow edge:** There will be self-edges for each node keeping the number of non-conflicted targets for each orientation.





- Actually without looking at the targets, we can get the total knowledge of lonely targets and conflicted targets.

- **In greedy-approach,** when a sensor and its orientation is selected the targets covered by that orientation of the sensor should be removed from the sensors which also cover those targets. For this task, whole set of remaining sensors should be checked.
- **In our model,** the task become localized. When we select a sensor, we know the sensors with which the sensor has conflict.

- The localized search will reduce the run time than the greedy one.

COMPARISON OF DIFFERENT HEURISTICS

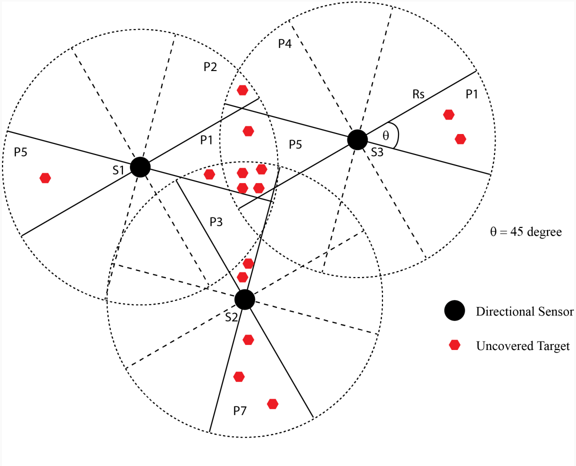


Figure: An example scenario

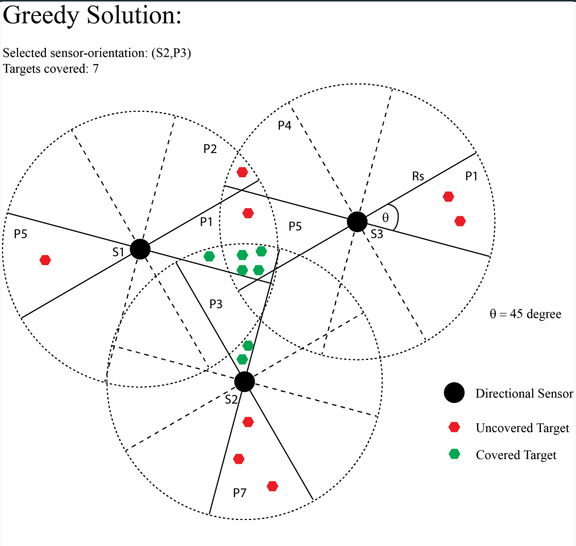


Figure: Greedy Step 01

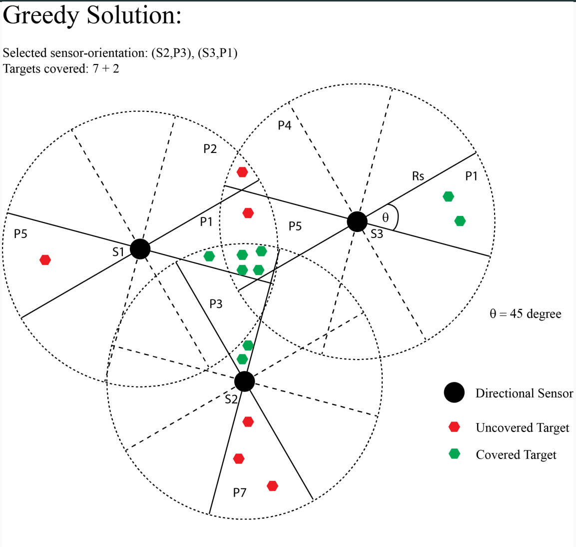


Figure: Greedy Step 02

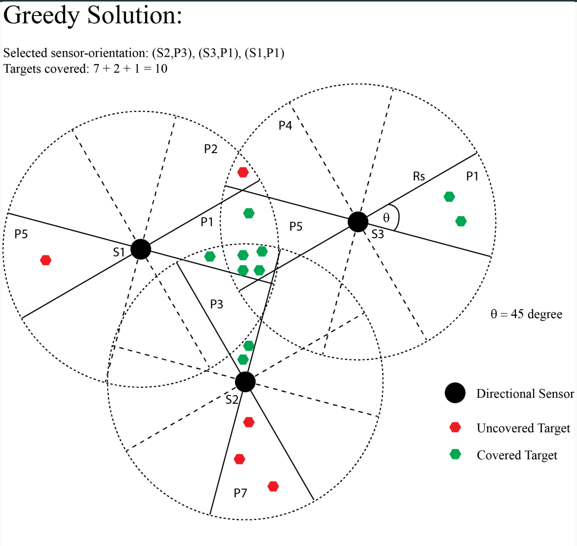


Figure: Greedy Step 03

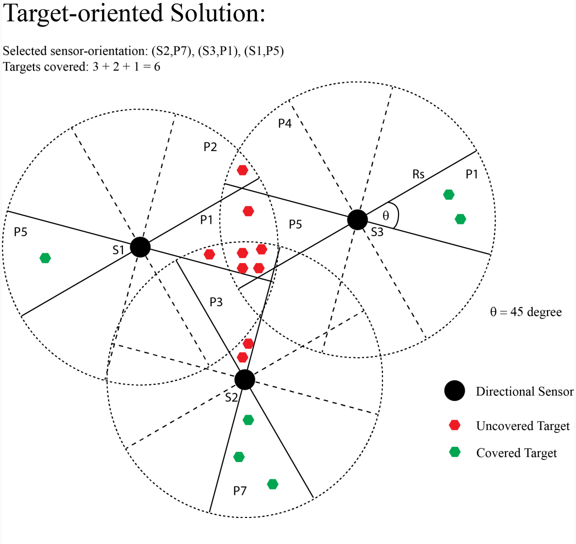
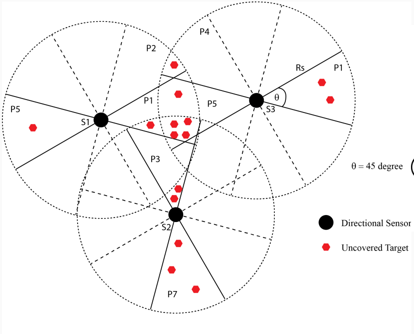


Figure: Target-oriented approach

COMPARISON OF DIFFERENT HEURISTICS



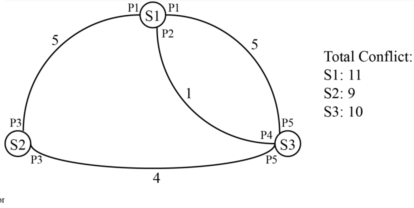


Figure: Modeling conflict graph

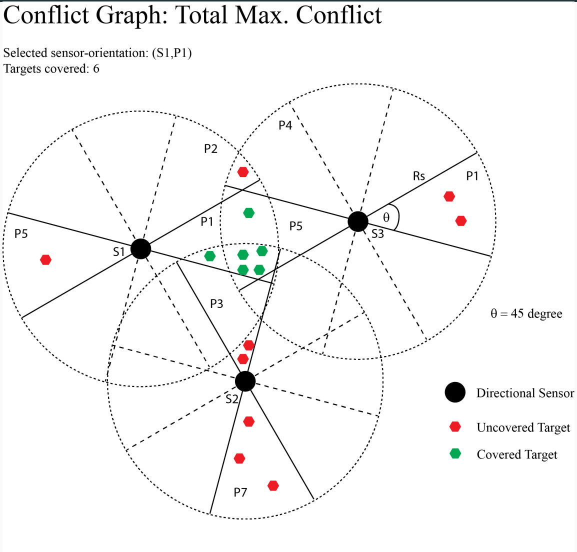


Figure: Conflict graph approach step 01

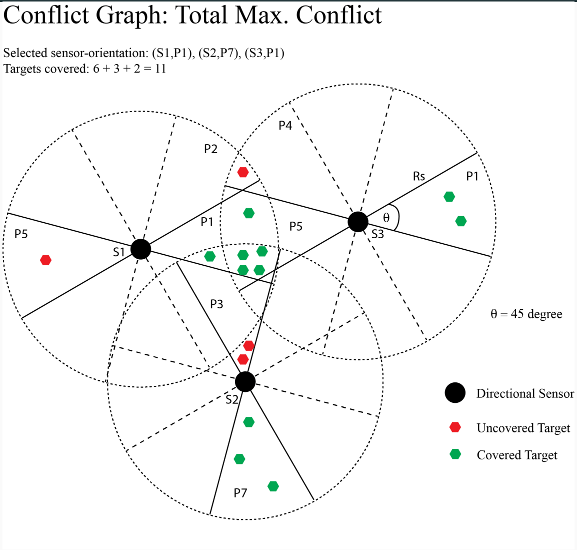


Figure: Conflict graph approach step 02 and 03

COMPARISON OF DIFFERENT HEURISTICS

Heuristics	Coverage (out of 15 targets)
Greedy	10
Target-oriented	6
Conflict graph	11

CONCLUSION

CHALLENGES

- We have to model the conflict-graph beforehand.
- We have to formulate different heuristics suitable for applying to our graph model

FUTURE WORK PLAN

- Formulate different new heuristics suitable to apply to our graph model .
- Evaluate performance of the new heuristics and compare them with the existing one's.

SUMMARY

- Add new dimension to look at the problem and generate corresponding solution.
- Graph approach will open new doors to explore the problem space for finding better solutions.
- We can apply different heuristics to our graph modeling.

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Thank You!

Questions?