

DEVELOPMENT OF LOCAL POSITIONING SYSTEM FOR A PIPE-LESS PLANT

Automation & Robotics
Group Project SS18

Group Members:

Abdulrahman Abouelkhair(198803)
Medhini Rajagopal Balamurugan(198735)
Stefan Rottstegge(191455)
Stephan Vette(198907)

Supervisors:

Afaq Ahmad
Marina Rantanen-Modéer

Abstract

The pipe-less plant at the Process Dynamics and Operations group is an experimental setup of Automated Guided Vehicles (AGVs) moving between various stations. The AGVs dynamically change trajectories in an operational mode based on a Model Predictive Control (MPC) scheme with the objective to get from one station to the other while at the same time avoiding each other. The current positioning system is based on pattern recognition where the system tracks each AGV based on a unique pattern of LEDs via a camera that overlooks the plant. The vision-based positioning system displays some flaws and should be replaced by a system more adapted to the actual operational environment of the experimental plant.

The project aimed at first evaluating different potential positioning systems, selecting one of them based on defined metrics and then to develop a proof-of-concept based on the chosen technology for the experimental pipe-less production plant in a model-driven fashion and the Radio-Frequency Identification (RFID) was chosen for further evaluation and implementation. The system uses RFID tags are embedded with a transmitter and a receiver. When the tags are within the range of the reader, the reader receives the unique ID and the RSSI (Received signal strength indication) of the tag which is being used for calculating the position of the robot.

For the estimation part, the WiFi module then transmits the reader data through the local network, using TCP/IP communication. The system data is lastly received by a PC that represents the control hub of the plant through a framework implemented in C Sharp (C#). The algorithm calculating AGV position prompts for this data as position and/or orientation of an AGV needs to be computed.

Contents

1	Introduction	7
2	Pipeless plant	9
2.1	Existing setup	9
2.2	Problems with the Existing Setup	10
2.3	Project Objectives	10
3	Possible localization technologies for chosen application	11
3.1	Triangulation	11
3.2	Pattern Recognition	15
3.3	Map-Based Localization[1]	17
3.4	RFID	20
4	Principle of localization via Radio Frequency Identification technology	23
4.1	Radio Frequency Identification	23
4.1.1	RFID System	23
4.1.2	Working Principle	23
4.2	Trilateration	25
5	Hardware	27
5.1	RFID reader and antenna	27
5.2	RFID tag	28
5.3	Wifi Module	29
5.4	Hardware Setup	30
6	Simulation	32
6.1	Emulator	32
6.2	RSSI Measurements with real hardware	33
6.3	Simulation with emulated data	34
6.4	Results	34
7	Implementation	35
7.1	Communication	35
7.2	Initialization procedure	37
7.2.1	Recording and filtering data	41
7.2.2	Analysing data	41
7.2.3	Selection of correct distance related to RSSI	42
7.2.4	Estimation of initial position and orientation	44
7.3	Test setup	45
7.4	Results	47
8	Conclusion	49
9	Future work	50
9.1	Hardware	50
9.2	Software	50
10	References	51

11 Appendixes	53
11.1 Appendix A: Emulator RFID data (Matlab)	53
11.2 Appendix B: Receiving data from reader via Wifi (C#)	57
11.3 Appendix C: Initialization procedure (C#)	61
11.4 Appendix D: Initialization turn and recording Data(C#)	61
11.5 Appendix E: Filling Array(C#)	63
11.6 Appendix F: Checking for solutions in array(C#)	64
11.7 Appendix G: Position and orientation estimation(C#)	67
11.8 Appendix H: Initialization procedure 3(C#)	70
11.9 Appendix I: Initialization procedure 4(C#)	72
11.10 Appendix J: Initialization procedure 5(C#)	72
11.11 Appendix K: Initialization procedure 6(C#)	73
11.12 Appendix L: Initialization procedure 7(C#)	79
11.13 Appendix M: WeMos D1 Mini (Arduino)	81
11.14 Appendix N: Communication Outlay	85

List of Figures

1	Existing setup	9
2	Passive triangulation setup with two cameras [3]	11
3	Active triangulation	12
4	Implementation of passive triangulation	13
5	Ceiling with periodic patterns of lamps acting as landmarks.	15
6	Belief grid of the robot in the plant	16
7	Snapshot of the ceiling	16
8	Adaptive Monte Carlo localization	17
9	Global Map	18
10	Local Map	18
11	Robot Orientation	18
12	Correction with global map	18
13	Passive RFID System	20
14	Active RFID System	20
15	Reader Tag	23
16	RFID System	24
17	Inductive Coupling	24
18	Overview Trilateration	26
19	RFID reader KTS Systeme RFIDM1356-001	27
20	RFID Antenna KTS Systeme PCBA1356_8	28
21	Paper Tag	29
22	Tags on the plant floor	29
23	WeMos D1 Mini WiFi Module	29
24	Robot Hardware Schematic	30
25	Hardware Schematic	30
26	Top of the Robot	31
27	Base of the Robot	31
28	Relation between RSSI and distance antenna to tag	33
29	RFID-WeMos Module Communication	35
30	WeMos Module Network Communication	36
31	Computer Network Communication	36
32	Different possible positions for one antenna position	37
33	Possible hazards/obstacles	38
34	Flow Chart: Initial procedure 360° turn	39
35	Test environment in GUI	39
36	Flow Chart: Analyzing measurement points	42
37	Flow Chart: Selection of correct distance and most proper IDs	43
38	Computing the center of the robot	45
39	Orientation of robot in absolute angle	45
40	Testing setup for initialization procedure	46
41	Estimated position in x-direction	47
42	Estimated position in y-direction	48
43	Estimated orientation	48
44	Communication Outlay	85

List of Tables

1	Pros and cons points of passive triangulation	14
2	Pros and cons points of active triangulation	14
3	Pros and cons points of Mobile Robot Localization based on Pattern Recognition	16
4	Pro and cons of Localization using Ultrasonic Sensor	19
5	Overview RFID systems	21

6	Pro and cons of active RFID system	22
7	Pro and cons passive RFID system	22
8	Relation between RSSI and distance antenna to tag (data)	33
9	Results Simulation	34
10	Filled array after 360° turn	40
11	String preperation	41
12	Possible shapes of pattern	43
13	Positions of the IDs in the test setup	46

1 Introduction

In today's world, the development and implementation of the positioning system for the autonomous vehicle in a confined space remains to be a major issue and hindrance to a better control system. Though there exists many types of local positioning systems, the precision remains to be still a challenge. This problem becomes critical in a place of no GPS access. This project aims at investigating various methods of indoor localization and to develop a proof-of-concept for the existing pipeless plant setup.

In the past years students and researchers at the Process Dynamics and Operations group at the TU Dortmund have developed this plant with vision based positioning system which need to be replaced to improve the overall efficiency of the system. Both the old and newly implemented techniques are written in C# that sends the position update to the Python based controller code.

In this project, various potential positioning techniques were discussed and their pros and cons were compared. The different localization methods would be further discussed in section 3. After a thorough four different alternatives including a triangulation based methods for indoor applications, another pattern recognition based method (such as QR-codes), map-based localization, *Radio Frequency Identification* was chosen to be the ideal technique. It is a versatile technology with multiple application areas, e.g. access control, race tracking and positioning. Automated multi-agent systems are increasingly utilizing RFID for localization as the technology has been proven to have many advantages over vision based positioning systems 4. There are two potential ways to implement an RFID localization system namely active and passive. The latter is based on comparatively many passive tags, uniformly placed, on the ground of the plant area and active readers on the AGVs. The latter option was chosen for the project based on cost efficiency, system scalability and from literature proven applicability.

An RFID system is made up of two parts: a tag and a reader. RFID tags are embedded with a transmitter and a receiver. The RFID component on the tags has two parts: a microchip that stores and processes information, and an antenna to receive and transmit a signal, which partly contains the unique ID of the tag. The hardware components which are added to the AGVs comprise an RFID antenna, an RFID reader and a WiFi module. Further hardware implementation is explained in section 7. The WiFi module then transmits the reader data through the local network, using TCP/IP communication. The system data is lastly received by a PC that represents the control hub of the plant through a framework implemented in C Sharp (C#). A TCP-Client was established in the C# framework in order to handle incoming RFID data. The WiFi-module continuously sends data and the algorithm calculating AGV position prompts for this data as position and/or orientation of an AGV needs to be computed.

The implemented positioning algorithm requires the ID and the received signal strength indication (RSSI) of at least three RFID tags to calculate the position of the antenna. The RSSI gives a relation between the detected tag and the distance to it, in other words, a radius. The system

has a record of the position of each tag and the ID of each tag hence holds information about the uniquely defined position of the tag. With three positions and the three corresponding radii, one can use trilateration to compute the position of the antenna. This concept was developed into simulation which would be discussed in section 6. The experiment bbbased results will be explained in 7. Based on the experiment, conclusion and future work are given in section 8 and 9 respectively.

2 Pipeless plant

In chemical industry, pipeless plants are used due to its high flexibility level. In these type of plants, *Automated Guided Vehicles(AGVs)* are used to transport the vessel from one processing station to another. Thus, for each and every batch, the AGV transport the vessel to various stations to create an end product, making the pipeless plant multi-product and multipurpose chemical production. In this way, piping and the associated cleaning is eliminated, thus aiding in cost and energy efficiency.

2.1 Existing setup

The pipeless plant framework in TU Dortmund, developed by the Process Dynamics and Operations Group (DYN), consists of four AGVs, two color stations, one mixing station and one storage station. Each station has a role in producing batch of plaster art, for example mixing or filling the product in the vessel. The stations and the AGV are controlled by a Programmable Logic Controller. The vessel on the AGV is moved from one station to another based on the schedule to produce a batch. Regarding the positioning system, the plant uses camera to identify the LED pattern on the AGV. Each AGV has a unique pattern that distinguishes it from another.

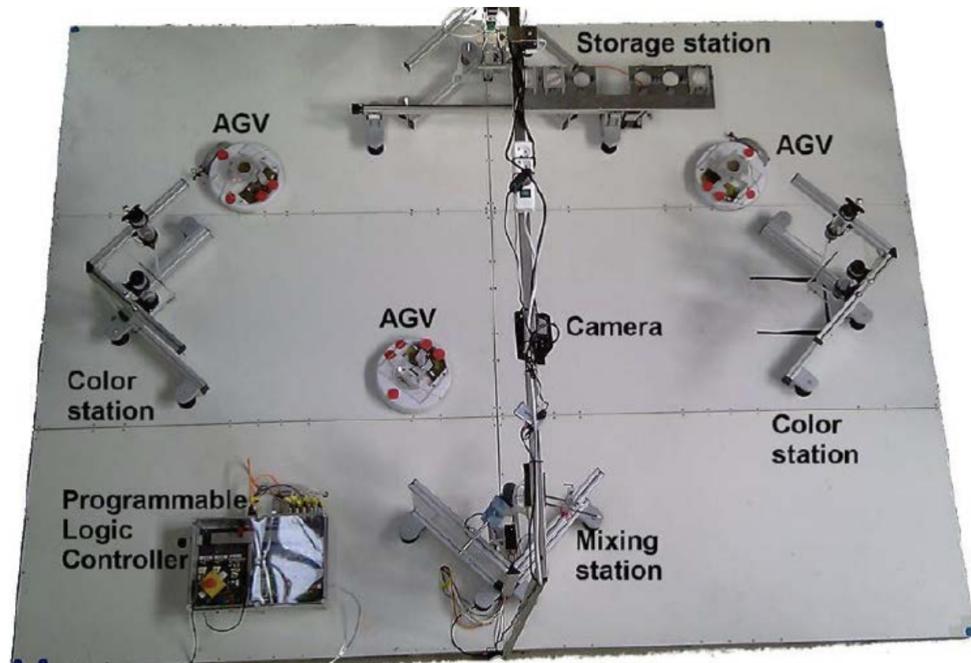


Figure 1: Existing setup

2.2 Problems with the Existing Setup

Since the existing setup uses vision based positioning system, the plant suffers various disadvantages as described below:

- During bright day-light conditions, no position is updated by the camera. This is due to the fact that the threshold of the sunlight and the LED on the AGV becomes equal that the camera fails to detect any pattern, thus affecting the whole system efficiency.
- The camera suffers the so called *fish-eye camera lense problem*, meaning that the position error is proportional to distance from the center of the image. This is caused by the distortion a wide angle lens.
- The restriction of usage of incoming information from the camera during software implementation.
- The percentage error and the processing time increases with the increase in number of robots to be localized thus affecting the controller input.

All these cons added up together cause a deterioration in the accuracy of the position of the AGV, which in turn affects the controller leading to a drop in system efficiency.

2.3 Project Objectives

The disadvantages of the vision based positioning system as discussed above leads to the urge for creating a localization that overcomes all the cons already suffered.

This project aims to research about alternative positioning system and to evaluate with selected method by simulation. The ultimate goal is to develop a positioning system with improved position precision and to compare and develop practical proof-of-concept.

3 Possible localization technologies for chosen application

Since the main aim of the project is to improve the positioning system of the existing setup, several other techniques were discussed, ending up in four methods namely *triangulation*, *pattern recognition*, *radio frequency identification*, *map-based localization*. The pros and cons were listed and the mentioned techniques were compared. The following section deals with a brief description of the above-mentioned techniques.

3.1 Triangulation

Since the plant has a specified size in which the location of multiple objects has to be performed the method of triangulation is one promising technic in which research was made. Triangulation was already a common principle of measurement in the 18th century and it is divided into active and passive triangulation. Passive triangulation is a geometrical method based on two measurement stations which positions are known exactly. At these two measurement points angels of the desired point in space are measured to compute the localization in the specified coordinate system (x , y , z) with trigonometrical formulas. With respect to the system setup used in the 18th century nowadays two cameras are installed to perform a geographical method of 3D object-data estimation as shown in fig. 2 [2].

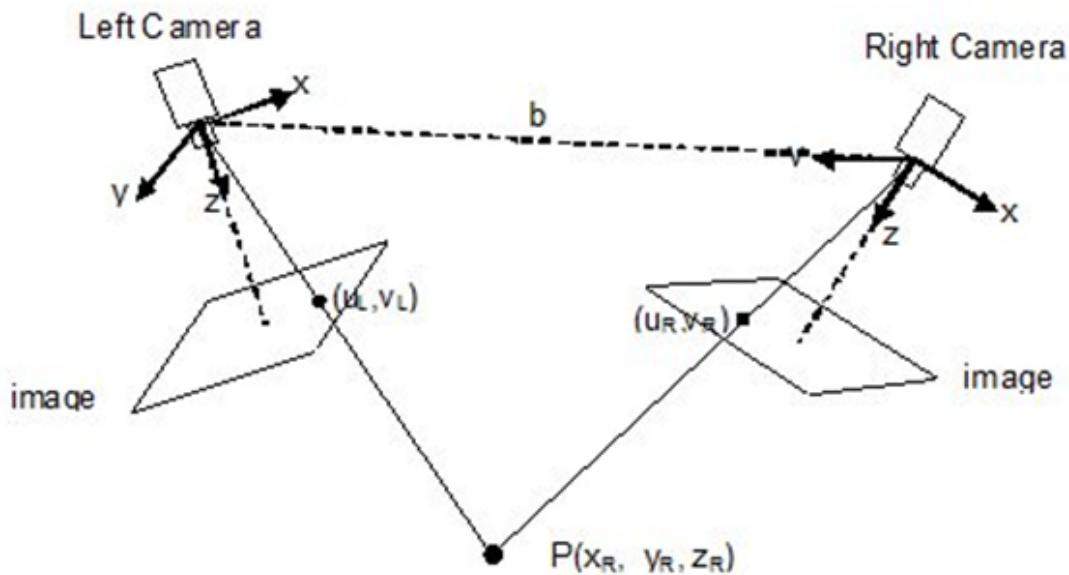


Figure 2: Passive triangulation setup with two cameras [3]

To solve the problem of position estimation, it is necessary to know the parameters of the left and the right camera visualized in the figure. In theory the triangulation is trivial, since each

and every point of the images of the respective cameras maps to a line in 3D space. If a pair of corresponding points, in the case of the pipesless plant it would be an AGV is found, the projection of a point x in 3D space can be computed. Active triangulation in comparison to passive triangulation needs one camera and at least one source of structured light (e.g. Laser). The geometrical location and orientation of the camera and light source in space need to be known. Two possible setups with either a laser point or a stripe as structured light are shown in fig. 3 [3][4].

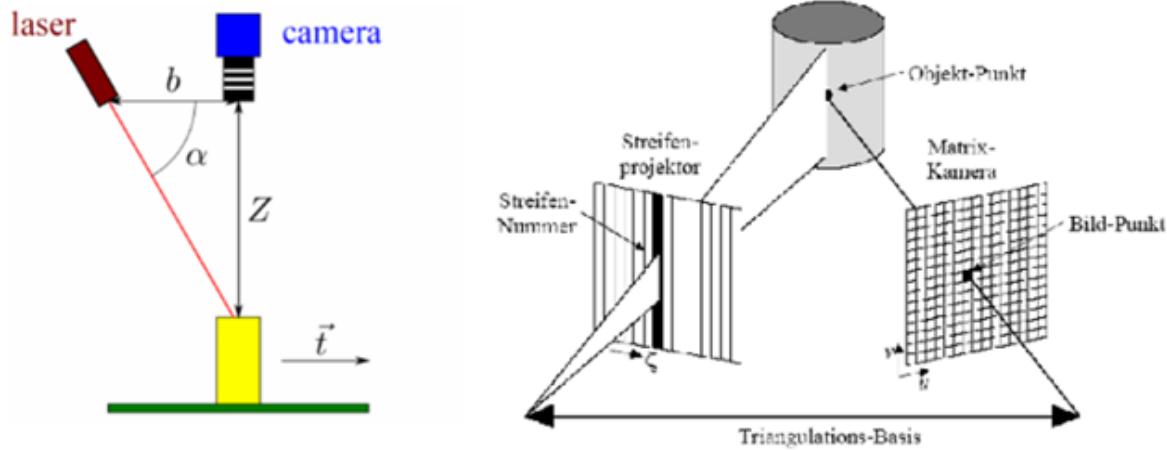


Figure 3: Active triangulation

To solve the active triangulation problem, the structured light has to point an object whose location is desired to estimate. If this point is found on the 2D image of the camera, a triangulation with basic trigonometrical formulas which are using the properties and parameters of the camera and light source can be performed and the position of the AGV can be estimated.

Implementation

One possible way to implement a solution for the passive triangulation is to attach 2 high resolution cameras with USB 3.0 on two edges of the plant as shown in fig. 4.

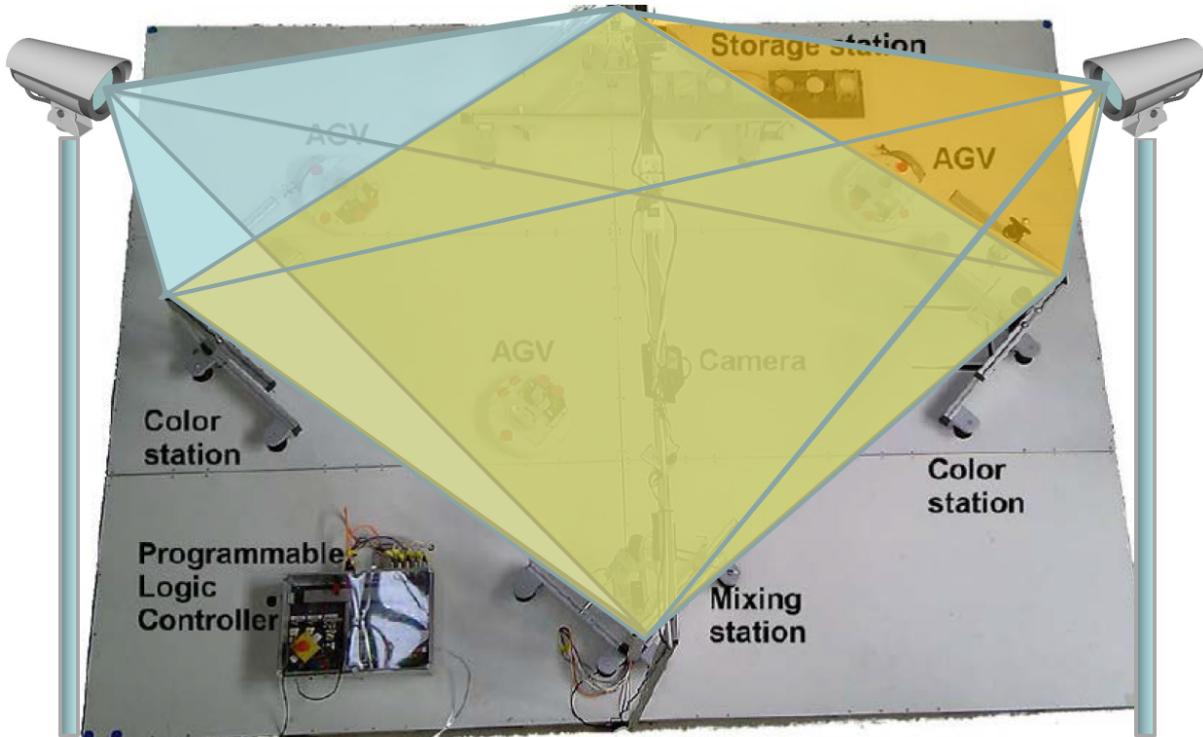


Figure 4: Implementation of passive triangulation

1

The left and right camera are sequentially taking pictures which are transmitted to the plants computer where the image processing takes place.

Based on the research made , two tables with advantages and disadvantages of the two triangu-

lation systems are created.

Passive Triangulation	
Pro	Con
Upgrade to USB 3.0 for faster data transmitting possible	Light dependent
Upgrade to a camera with higher resolution to reduce measurement error possible	New concept of orientation may be needed
No Fish-Eye-Lense problem	Limited range of observation
Low cost	

Table 1: Pros and cons points of passive triangulation

Active Triangulation	
Pro	Con
Upgrade to USB 3.0 for faster data transmitting possible	New unknown laser technology is needed
Upgrade to a camera with higher resolution to reduce measurement error possible	High costs for several lasers (one per AGV)
Easy detection of laser points on camera image	Laser needs to move while AGVs are moving
	Limited range of observation
	Light dependent

Table 2: Pros and cons points of active triangulation

3.2 Pattern Recognition

In this type of localization, estimation of the robot is done in indoor environments using only on-board sensors, namely a web-cam and a compass [5]. The ceiling of the plant is constructed with a pattern of static landmarks whose positions are known a priori as shown in fig. 5. All landmarks are indistinguishable from each other and might additionally be distributed along the ceiling in a periodic pattern. The landmark attached to the ceiling can be lights, QR codes, sensors or other reference points. The ceiling is used since it is immune to changes. A camera is installed on the robot, which takes snapshots of the ceiling which can be seen in fig. 7. The robot pose relative to the landmark is calculated with the help of the distance of the landmark to the center of the image and its angle relative to the direction of the robot motion. An IMU device is additionally used to give the absolute orientation of the robot in the plant. The Markov Localization (ML) algorithm is used to estimate the belief grid of the robot position inside the environment.



Figure 5: Ceiling with periodic patterns of lamps acting as landmarks.

Implementation

The goal is to compute the pose of a mobile robot inside an indoor environment using a camera and an IMU device. As mentioned, Markov Localization is used to create a belief grid of the robot in the plant environment. This is done with the help of the snapshots of the ceiling taken by the camera. As seen in the fig. 6, the blue and black areas have lower belief and green and

yellow areas have higher belief. The obtained pattern is evaluated and based on the pattern, the position of the robot is estimated. Thus with the help of the camera and the IMU device, both the position and orientation is obtained.

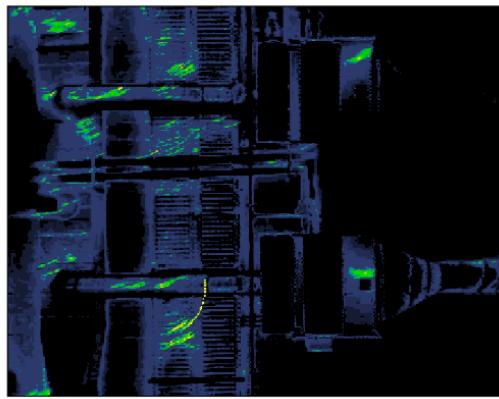


Figure 6: Belief grid of the robot in the plant

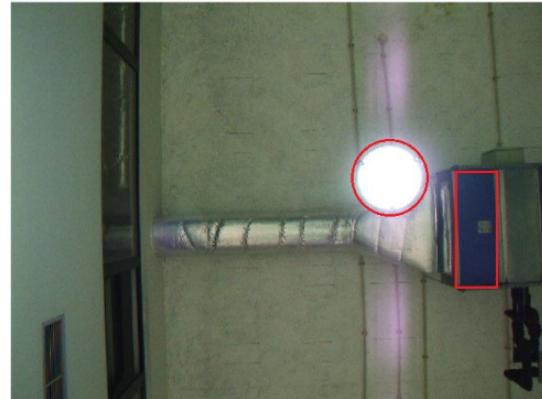


Figure 7: Snapshot of the ceiling

Based on the research, the advantages and disadvantages of Mobile Robot Localization based on Pattern Recognition are created.

Pro	Con
The ceiling is usually immune to changes as a reference and implement landmarks on the ceiling itself	Complex and many changes have to be added to the plant
No Fish-Eye-Lense problem	Cost intensive
	Light dependent

Table 3: Pros and cons points of Mobile Robot Localization based on Pattern Recognition

3.3 Map-Based Localization[1]

Adaptive Monte Carlo Localization (AMCL) is a probabilistic localization system for a robot moving on a two dimensional surface. It implements the adaptive (or KLD-sampling) Monte Carlo localization[7][8] approach, which uses a particle filter to track the pose of a robot against a known map.

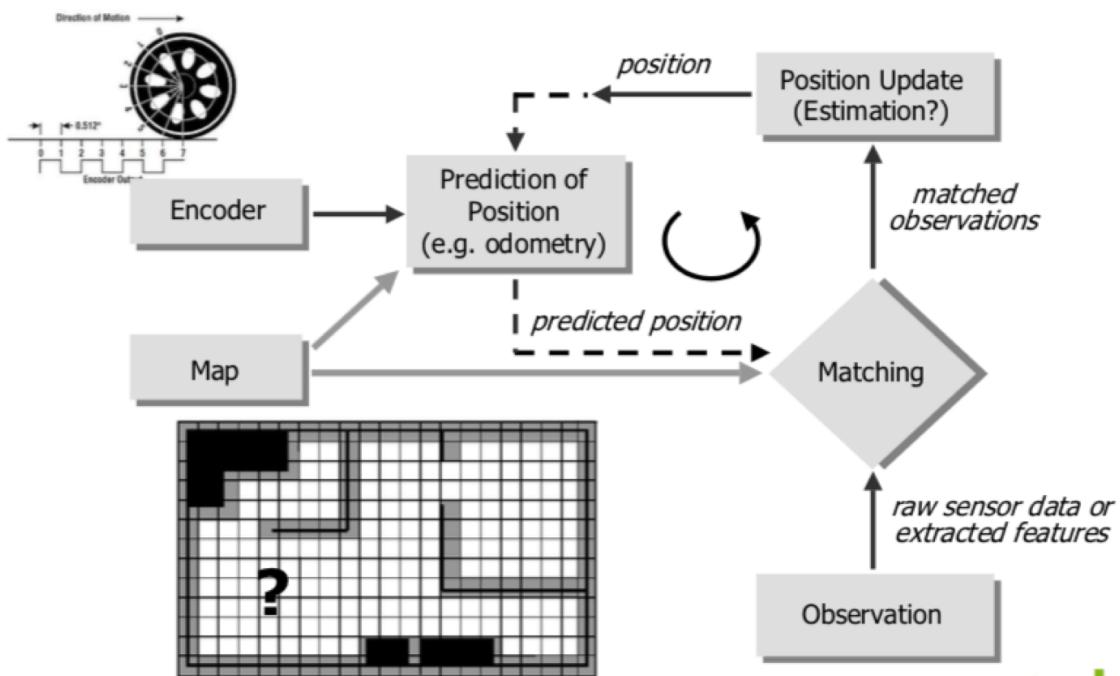


Figure 8: Adaptive Monte Carlo localization

AMCL takes in a laser-based map, laser scans, and Odom scan, and outputs pose estimates (see fig.8). On startup, amcl initializes its particle filter according to the parameters provided. Note that, because of the defaults, if no parameters are set, the initial filter state will be a moderately sized particle cloud centered about (0,0,0).

Implementation

To implement such a technique a global and local map should be created as shown in fig. 9 and fig. 10, following are the steps for creating robot localization based on a map.

- SLAM (Simultaneous Localization and Mapping) is a technique used in mobile robotics in which a robot builds a map of an unknown environment, keeping at the same time track of its localization in this environment.

¹Source of figure 8 (Adaptive Monte Carlo localization): www.moodle.tu-dortmund.de/mobile-robots



Figure 9: Global Map

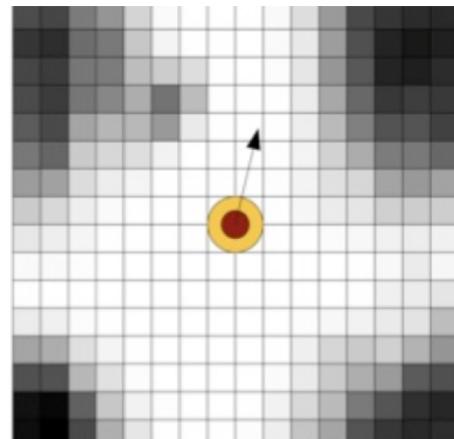


Figure 10: Local Map

- Adaptive Monte Carlo Localization

Given a map of the environment, the goal of the algorithm is for the robot to determine its pose within the environment.

At every time t the algorithm takes as input the previous belief $X_{t-1} = \{x_{t-1}^1, x_{t-1}^2, \dots, x_{t-1}^M\}$, an actuation command u_t , and data received from sensors z_t ; and the algorithm outputs the new belief X_t .

- Orientation Correction

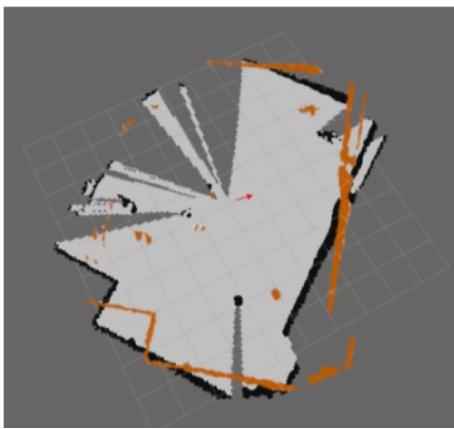


Figure 11: Robot Orientation

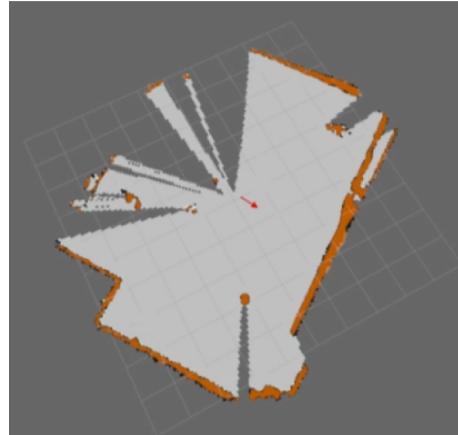


Figure 12: Correction with global map

Initially the robot assumes a position as shown in fig.11, and as it moves it begins to

¹Source of figures 10, 9, 11 and 12: www.moodle.tu-dortmund.de/mobile-robots

re-correct it's estimated orientation using the static obstacle with the global map as a reference as shown in fig. 12.

Based on the research made, two tables with advantages and disadvantages of the two Map-Based Localization systems are created.

Using Ultrasonic Sensor	
Pro	Con
Cheaper than the other localization techniques with €3 per each Ultrasonic sensor	Multiple Ultrasonic sensors need to be installed on a single robot due to very small scan angle ranging 30°
Easy installation of the sensors on the robot due to small size	A plant installation with similar landmarks causes localization error using AMCL
Ultrasonic sensors have faster feedback than the previous camera based localization system	Large plant size causes high computational effort for AMCL
Ultrasonic sensor has large scan range of 4.5 meters	Robots should start at every launch from static home position
Different map based localization algorithms are available	

Table 4: Pro and cons of Localization using Ultrasonic Sensor

3.4 RFID

One of the possible solutions to solve the challenging problem of indoor localization is the use of the Radio-frequency Identification (RFID) technology. The main areas of this technology is indeed still supply chains, transport, manufacturing, personnel access, animal tagging, toll collection [6], but also has become popular in localizing objects and persons. Where in the main applications only the identification has to be realized, also the strength of the signals is important to estimate the position of a certain object.

The main idea of those systems is that a reader detects a tag and reads its information. The technology can be divided into three main types: passive, semi-passive and active systems. A passive system, like it is been shown in fig. 13, consists of a reader, which is connected to an antenna and a computer and a passive tag.

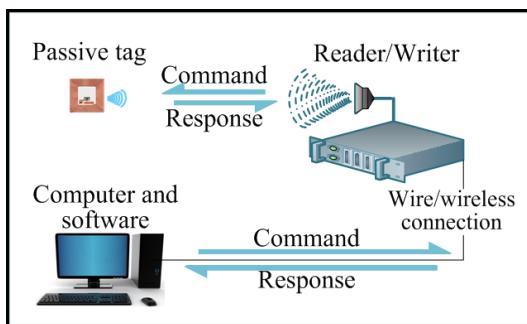


Figure 13: Passive RFID System

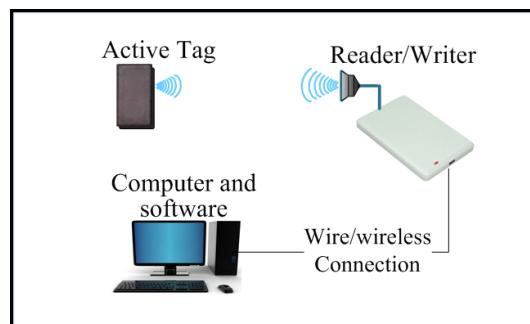


Figure 14: Active RFID System

The system is called passive, because the power supply is realized by the radio signal of the reader. In case where the tag is in the reading range of the reader, the tag gets enough power to send predefined information (for example ID) back. The active system (see fig.14) in comparison has an active tag which has an own power supply. The semi-passive tag has a battery build in that the tag has more power to communicate, but is not used to generate radio frequency signals.

Another classification of RFID systems is the frequency of the radio waves. It can reach from 0.135 MHz (Low Frequency) to 5875 MHz (Super High Frequency). The table 5 gives an overview about the systems related to reading ranges, reading rates and the ability to read near metal or water.

It can be seen that the passive systems in general have a smaller reading range than the active systems and has a bigger data rate. But it has also to be taken into account, that passive tags are cheaper than active tags.

	LF	HF	UHF	SHF
FR (MHz)	< 0.135	3~28	433-435, 860-930	2400~2454 5725~5875
RR(P)	≤ 0.5 m	≤ 3 m	≤ 10 m	≤ 6 m
RR(A)	≤ 40 m	300 m	≤ 1 km	≤ 300 m
TRR	Slower	↔		
ARMW	Better	↔		
FR: Frequency Range RRP: Typical Reading Range of Passive Tags RRA: Typical Reading Range of Active Tags TRR: Tag Reading Rate ARMW: Ability to Read near Metal or Water				

Table 5: Overview RFID systems

Implementation

There are mainly two different ways to realize a localization system of the AGVs in the pipeless plant. Based on the fact that the plant has a size of 3 by 4 meter, the tracking can be carried out with a passive system in which a couple of passive tags on the floor can be used as landmarks. In this case the reader plus the antenna would be placed on the AGV and localize with the help of the detected tags. The other systems consists of three or four reader in each corner of the plant and an active tag on each AGV. Based on the research made, two tables with advantages and disadvantages of the two RFID systems are created.

Active RFID system	
Pro	Con
Light independent	Prototype more expansive (3 reader + active tags)
Space unlimited	Datarate is related to the amount of detected tags at the same time
Localization only has to be realized in a bigger area - medium accuracy	Anticollision need, cause more AGVs are used at the same time
Wired communication between reader and computer possible	Signal strength can be influenced by environment (metal or water)
Simple algorithm (Trilateration)	

Table 6: Pro and cons of active RFID system

Passive RFID system	
Pro	Con
Light independent	Communication between AGV and computer has to be realized
Space unlimited	Data rate is related to the amount of detected tags at the same time
Localization only has to be realized between four tags (small area) - high accuracy	Anticollision need, cause more tags are detected at the same time
Simple algorithm (Trilateration)	
Prototype cheap (1 reader + passive tags)	

Table 7: Pro and cons passive RFID system

4 Principle of localization via Radio Frequency Identification technology

4.1 Radio Frequency Identification

After in depth analysis of various localization methods the Radio Frequency Identification[9][10] was chosen due to its various advantages. This technology involves a reader and a tag which is placed on the object to be tracked. The reader is continuously sending the radio waves, and when the tag is within the range of reader, it sends a feedback signal to the reader as shown in fig. 15. The reader can track multiple tags at the same time.

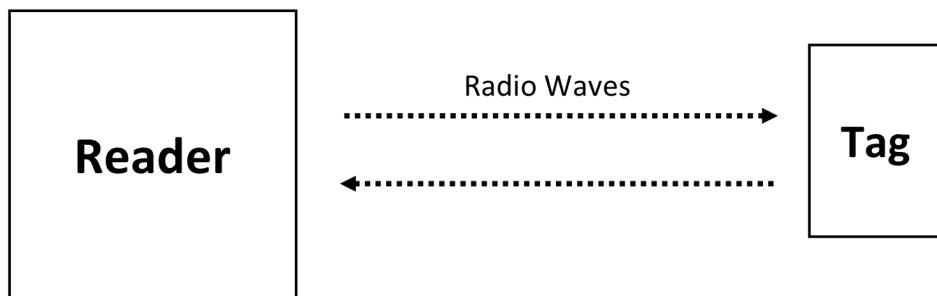


Figure 15: Reader Tag

4.1.1 RFID System

Regarding the tags as shown in fig.16, it can be either

- Active tag which has its own power supply,
- Passive tag which relies on the radio waves as its source of energy that come from the reader ,
- Semi-passive tag which has power supply, but for transmitting the feedback, it relies on the signal coming from reader.

4.1.2 Working Principle

The RFID consists of three main parts:

- Generator which generates the radio waves.
- A signal detector which receives the feedback from the tag
- Micro-controller which processes the information from the generator and the detector

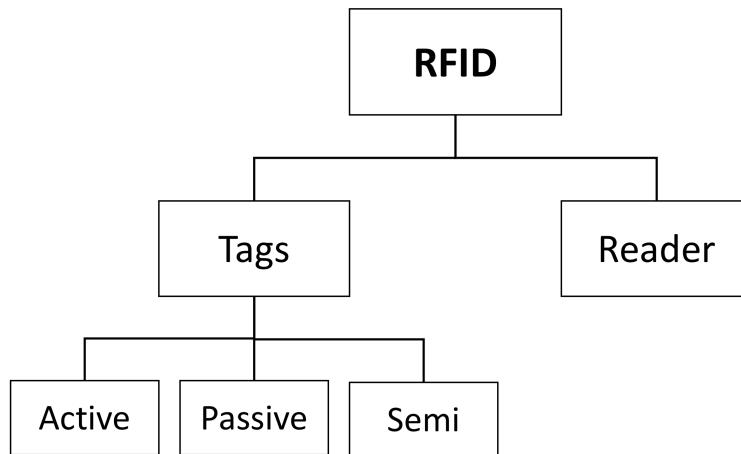


Figure 16: RFID System

The tags consists of:

- Transponder: that receives radio waves and sends the feedback
- Rectifier Circuit: which stores the energy coming from the wave across the capacitor, and this energy is used as a power supply for the controller as well as the memory

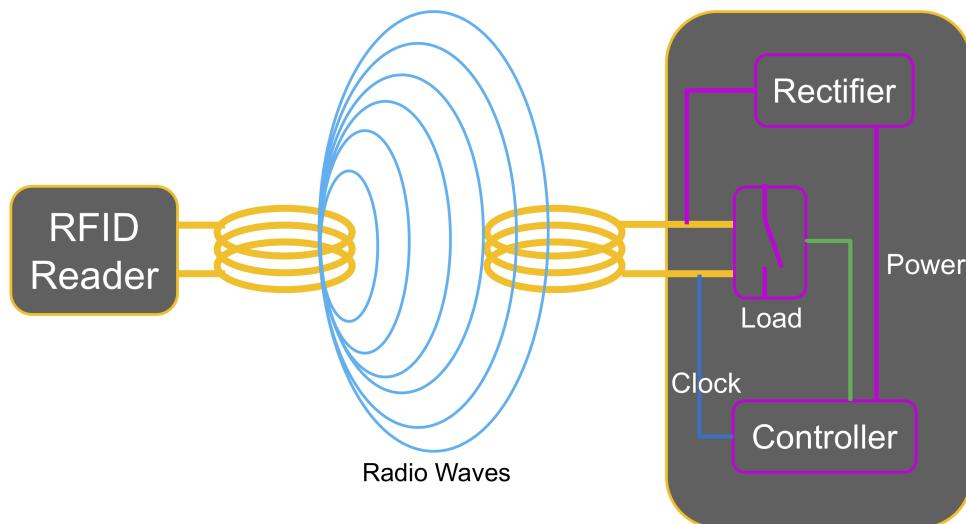


Figure 17: Inductive Coupling

The whole process of sending the information between the tag and the reader is based on principle of "Inductive coupling" as shown in fig. 17. The reader is continuously sending radio

waves with particular frequency. In this case, the reader and the tag should be close to each other. The field which is generated by the reader is used coupling antenna of the tag, and due to the mutual coupling, the voltage is induced across the coil of tag. The voltage is rectified and used as power supply for the controller and is used to derive synchronization clock for the controller.

When the load circuit is connected to the coil, the current starts flowing through the load. Therefore, when the load is switched on and off, the current will be turned on and off respectively leading to the induction of particular voltage in the reader. This method of switching the load is called load modulation. Thus, with the help of load modulation with respect to the data stored in the tag, the value of the induced voltage can be modified, leading to the generation of modulation on carrier frequency, thereby sending the data to the reader.

4.2 Trilateration²

Trilateration is a method to compute the intersection point of three circles/spheres. For this, it is necessary to know the three center of the circles/spheres plus their corresponding radii. The basic idea to estimate the intersection point is to use the mathematical description of a sphere:

$$r^2 = (x - x_1)^2 + (y - y_1)^2 + (z - z_1)^2 \quad (1)$$

where ($P_n = (x_n, y_n, z_n)$) is the center of the sphere [11]. A few assumption can be made to simplify (1) for the 2D indoor localization on a floor. First of all, the z-component of all spheres can be neglected. Another assumption is that we define the origin of the first circle as the center of the coordinate system, the second along the x-axis with a distance (d) and the third shifted in x- (i) and y-direction (j), which is illustrated in following fig.

With known positions of the center of the circles d, i and j can be computed in the following way[11]:

$$d = |P_2 - P_1| \quad (2)$$

$$e_x = \frac{1}{d}(P_2 - P_1) \quad (3)$$

$$a_x = P_3 - P_1 \quad (4)$$

$$i = e_x \cdot a_x \quad (5)$$

$$a_y = (P_3 - P_1) - i * e_x \quad (6)$$

$$e_y = \frac{a_y}{|a_y|} \quad (7)$$

$$j = e_y \cdot a_x \quad (8)$$

It has to be notice that P_1, P_2 and P_3 are 2D vectors, which represents the x- and y-coordinate of the points.

²Stephan

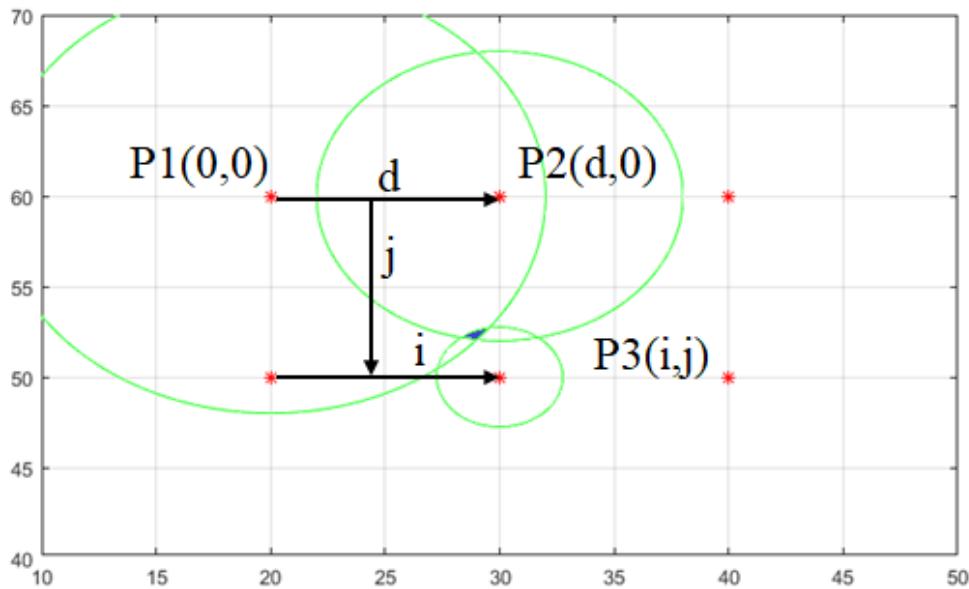


Figure 18: Overview Trilateration

After knowing these values, the relative distance from the origin of the coordinate system can be computed with the help of (1) and the center of the circles $P_1(0,0)$, $P_2(0,d)$ and $P_3(i,j)$ as follows:

$$x_t = \frac{r_1^2 - r_2^2 + d^2}{2 * d} \quad (9)$$

$$y_t = \frac{r_1^2 - r_3^2 + i^2 + j^2}{2 * j} - i * \left(\frac{x_t}{j} \right) \quad (10)$$

The absolute position of the intersection point is computed in following way:

$$P = P_1 + e_x * x_t + e_y * y_t \quad (11)$$

It can be seen, that those equations are using the first two points plus radii to estimate the x-coordinate and first and third point plus the estimated x-coordinate to estimate the y-coordinate.

5 Hardware³

5.1 RFID reader and antenna⁴

The RFID reader from KTS Systeme (see fig.19) is a HF Modul (frequency around 13.56 MHz). It contains a full-fledged microcontroller with a high-performance RFID transceiver IC. It has a 1.27 mm pitch pin-headers for THT mounting. The connection to an external antenna can be realized via a Single ended 50Ω connection or via Pin Header U.FL. jack, which was used in this project.

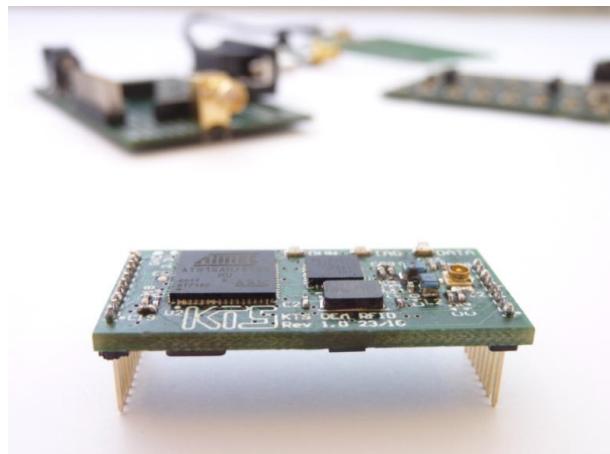


Figure 19: RFID reader KTS Systeme RFIDM1356-001

The communication to other devices is realized via a UART compatible serial interface via pin 6 (RX) and 7 (TX). The power supply is a 5 V DC connection via pin 1 (VCC) and pin 10 (GND). The reader is standardized to ISO 15693 and ISO14443A/B and has the overall dimensions 36 x 16 x 4 mm [LxWxH][12].

The reader has three LEDs:

- Green: Run - Lights when reader receives power
- Yellow: Tag - Lights when a tag is detected
- Red: Data - Lights when data transfer to or from a tag

To configure the reader, KTS Systeme also provides a software (Tag2Image) for free. The reader was configured to scan the environment in an automatic anti collision mode (AT+Scan=AC,RSSI). Anti collision means that multiple tags can be detected at the same time and is highly important in this project. The output of the scan is a continuous information of the Identification (ID) and the Received Signal Strength Indicator (RSSI) of the detected tags. For example: SCAN:+UID=E00402000018313E,+RSSI=7/6 means that the tag with

³Stephan

⁴Stephan

the ID (in hex) E00402000018313E was detected with a RSSI of 7/6. For the RSSI is the first number the value for the main and the second for the auxiliary receiver channel. In this project only the first number of the RSSI was used. The RSSI is an integer value from 0 to 7 and gives an information about the distance between the antenna and the detected tag. 0 stands for the maximum reading range which was mentioned to be around 15 cm. A detailed relation was figured out experimental during the project and will be explained later in this report. An AT Command Reference Guide is also available on <http://rfid.kts-systeme.de/downloads/>.

The antenna (fig. 20) is a HF PCB Antenne (PCBA1356_8) also from the company KTS Systeme. It has a dimension of 80 x 80 mm. The connection to the reader is realized by a SMA jack and has a self-impedance of 50Ω . The antenna is designed for passive tags in a frequency range around 13.56 MHz and has a maximum power of 1W.



Figure 20: RFID Antenna KTS Systeme PCBA1356_8

The antenna and the reader are connected with a SMA to U.FL. adapter cable.

5.2 RFID tag

The tag used in the prototype is of paper type (see fig.21) due to its added advantages as follows:

- The tags are cheap costing 18 cents each.
- It doesn't require power supply.
- The tags are compact.
- The implementation in the time of plant extension is simple.

It's working principle is based on inductive coupling with an operating frequency of 125-135 kHz and a range of 10cm. The tags are fixed on the floor at known location as shown in fig.22.

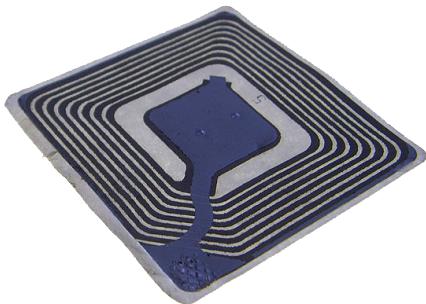


Figure 21: Paper Tag

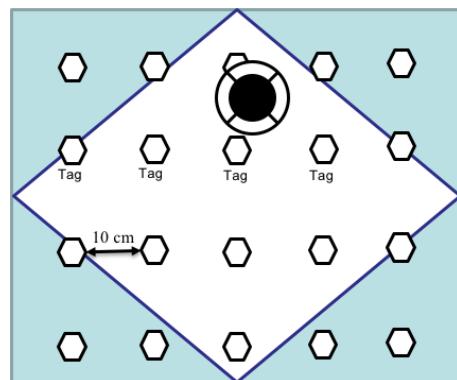


Figure 22: Tags on the plant floor

5.3 Wifi Module

The WiFi module used is from WEMOS Co.[13].It is a mini WiFi board with 4MB flash based on ESP-8266 which is a WiFi microchip with full IP/TCP stack and micro-controller (see fig.23).

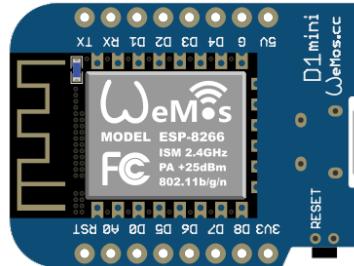


Figure 23: WeMos D1 Mini WiFi Module

The WeMos module has the following features:

- 32-bit RISC microprocessor core running at 80 MHz
- External QSPI flash of 4 MB
- IEEE 802.11 b/g/n Wi-Fi
- 16 GPIO pins
- UART on dedicated pins, plus a transmit-only UART can be enabled on GPIO2

⁴Source of figure 21 (Paper Tag): www.kurzweilai.net/scientists-print-cheap-rfid-tags-on-paper

⁴Source of figure 23 (WeMos D1 Mini WiFi Module): www.github.com/mcauser/Fritzing-Part-WeMos-D1-Mini

- 10-bit ADC and I^2C (software implementation)

5.4 Hardware Setup

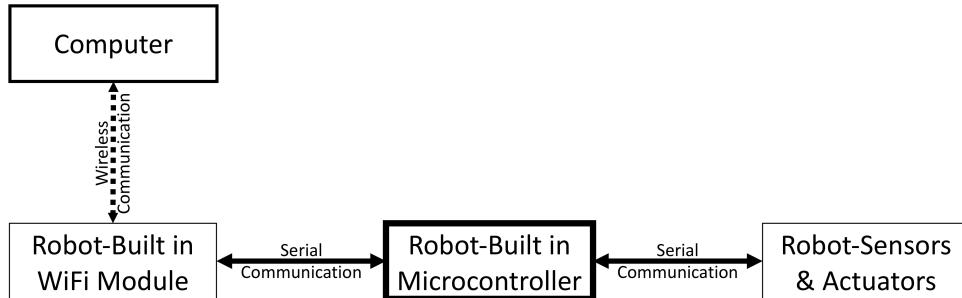


Figure 24: Robot Hardware Schematic

The built-in Micro-controller on the robot receives the sensor data and sends commands to the actuators via serial communication using its first UART pins. (TX/RX) is the process of sending and propagating an analogue or digital information signal over a physical point-to-point wired connection. It uses its second UART pins to communicate with the built-in WiFi Module. The built-in WiFi Module sends the received sensors data to the Computer and sends the received commands from the computer to the robot micro-controller via Wireless communication (see fig.24). Due to its less complexity, more flexibility and that the robot's in built micro-controller

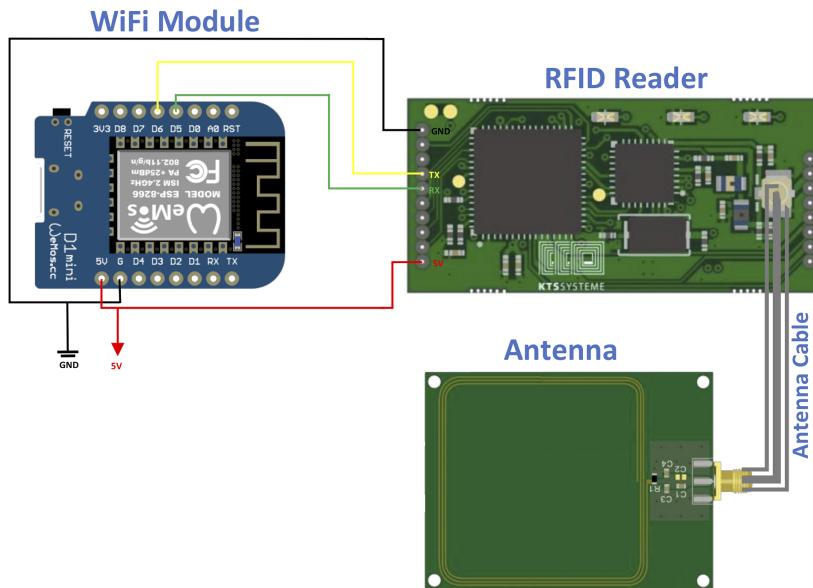


Figure 25: Hardware Schematic

UART pins are in use, a new communication setup was developed for the RFID reader to send the data from the robot to the computer in parallel to the robot hardware setup. As shown in fig.25) the RFID reader is connected directly to the built-in micro-controller of the WeMos WiFi Module via serial communication sending it the tags IDs. The WeMos WiFi Module sends the received data through the network. The RFID reader is connected to the antenna which sends and receives the radio waves via SMA antenna cable.

The RFID reader as well as WeMos Module are placed on the top of the robot while the Antenna is fixed to the robot base such that the radio waves would be in direct contact with the tags on the floor.



Figure 26: Top of the Robot



Figure 27: Base of the Robot

6 Simulation⁵

The simulation was carried out to answer important design questions before the real implementation phase. Furthermore artificial RFID reader data was created to test and simulate the algorithm, which will be explained in chapter 7.

To answer the design questions, the simulation has the following parameter (Appendix 11.1 Line 1-50):

- the size of the simulation space
- distance between the tags
- distance between the first/last row/column of tags and the border of the simulation space
- diameter of the robot
- position of the antenna related to the origin of the robot
- the relation between RSSI and the distance antenna and tag
- initial start position and orientation
- difference between the measurement points of the initialization procedure
- optional: cycle time and speed of the robot (for another procedure)
- logging parameter (look of the logged text file)

Foregone tests lead to a distance between the tags of 10 cm. This was founded on the fact that in this case at least 4 tags are detected at the same time (maximum reading range of 14 cm). In this case around 121 tags are needed for every square meter, which turned out to be realistic number for a small plant size.

6.1 Emulator

To create artificial RFID reader data, the emulator is able to write all detected tags together with information about the measuring point into a text file. During the initialization procedure, which was the main focus in this project, the robot turns around 360° and makes measurements every 45°.

The emulator computes the distance from the center of the antenna to the neighbouring tags at each measurement point. If a tag is closer than the maximal reading distance, the emulator writes the detected ID of the tag together with its RSSI into the text file.

The RSSI is, as explained earlier, an integer value from 0...7. 0 defines in this case a distance from 14 to around 10 cm from the antenna to the tag. In the first version of the emulator the RSSI is based on the information from the paper [14] and mentioned a consistent increasing of the RSSI while the distance between the tags and the antenna gets smaller.

During own measurements it has been found out that this relation is inconsistent. Therefore the second version of the emulator was updated and creates more realistic data.

⁵Stephan

6.2 RSSI Measurements with real hardware

The relation of the RSSI is not just related to the distance between the antenna and the tag. It also depends on the orientation of the plain of both components. The tests with the real hardware was performed in a setup where the tags were placed on a floor and the antenna was parallel to the floor at a hight of 1.5 cm. The reason for this was the fact that the antenna should be placed directly under the robot. Tbl. 8 and fig. 28 present the results of the measurements.

RSSI (Received Signal Strength Indicator)	0/0	1/1	2/2	3/3	4/4	5/5	6/6	7/7
Maximal distance antenna to tag [cm]	14	9.8	9	8	7	6	3.5	2.8
Middle distance antenna to tag [cm]	5	5.1	5.3	5.5	5.8	4	-	-
Minimal distance antenna to tag [cm]	-	4.7	4.5	4.3	4.2	-	-	-

Table 8: Relation between RSSI and distance antenna to tag (data)

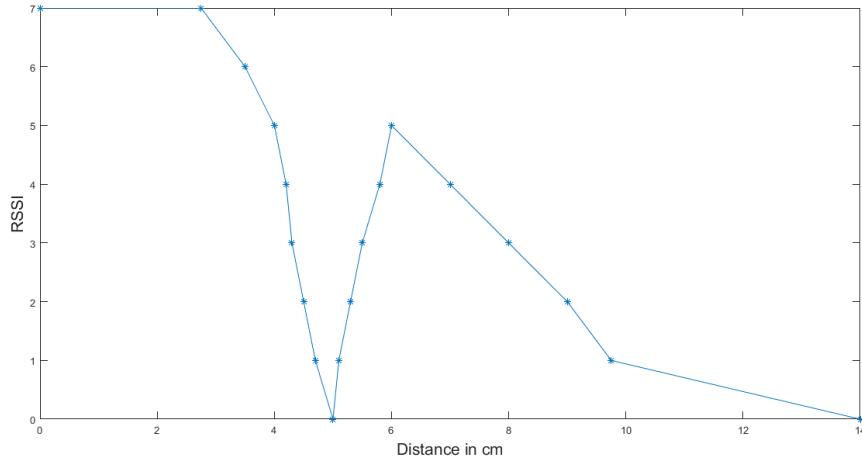


Figure 28: Relation between RSSI and distance antenna to tag

It can be seen that there exists a blind spot at a distance of 5 cm where the RSSI drops to 0. The consequence is that it is not trivial to build up a relation from the RSSI back to the correct distance.

6.3 Simulation with emulated data

The idea of the final implementation is to estimate the initial position and orientation of the robot. A first version of an algorithm to solve this problem is created in matlab. The first part of these algorithm is the emulator which simulates the 360° turn and records the tag information. The second part is the solver which is also explained deeper in the chapter 7. After observing an inconsistent behaviour of the RSSI the simulation as well as the solver were updated.

6.4 Results

The application of the emulated data on the solver indicates the following results:

	Avg. accuracy position (x-, & y-direction) [mm]	Avg. Accuracy orientation [°]
Data mentioned in paper	2	<1
Own recorded data (blind spot)	10	20

Table 9: Results Simulation

As can be seen from tbl. 9, there is a sufficient good match between the estimated position and orientation of the robot for the consistent RSSI data. On the other hand the inconsistent RSSI data results in significant differences in the estimation of the position and orientation of the robot.

The reason for this is the higher complexity of the algorithm to first estimate the correct distances related to RSSI values and then start to estimate the position based on those distances.

A small error in the estimation of the position of the antenna at the first measurement point leads also to a big error in the computed orientation of the robot.

7 Implementation

7.1 Communication

The already existing software is overwritten on the built-in micro-controller of the WeMos WiFi Module which was developed to have a continuous listening to all the data sent from the RFID reader even in case of no tags within the range. The complete and erroneous RFID data readings are as seen in the fig.29.

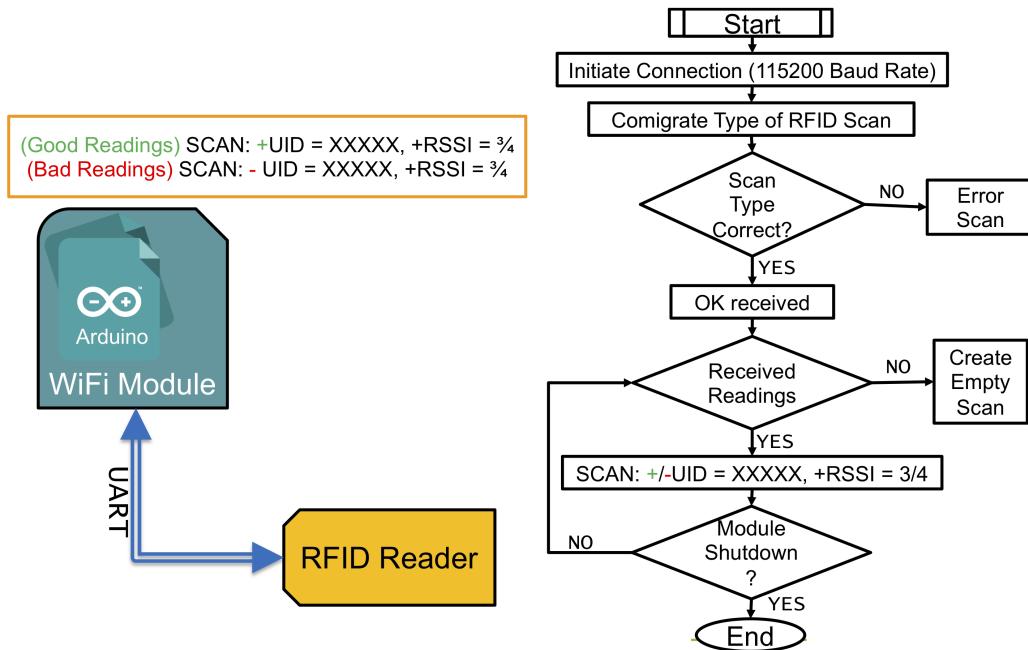


Figure 29: RFID-WeMos Module Communication

A TCP-IP communication is established within the network on the WeMos WiFi Module that start publishing the data which has been received from the reader. This communication is killed if and only if in the case of robot shutdown as shown in fig.30.

While on the other side of computer GUI (Graphical User Interface), the similar communication is being established (which should be on the same network). and should grasp all the data that has been published by the WeMos WiFi module even if there exists no feedback. This communication can be terminated on the GUI if required as shown in the fig.31.

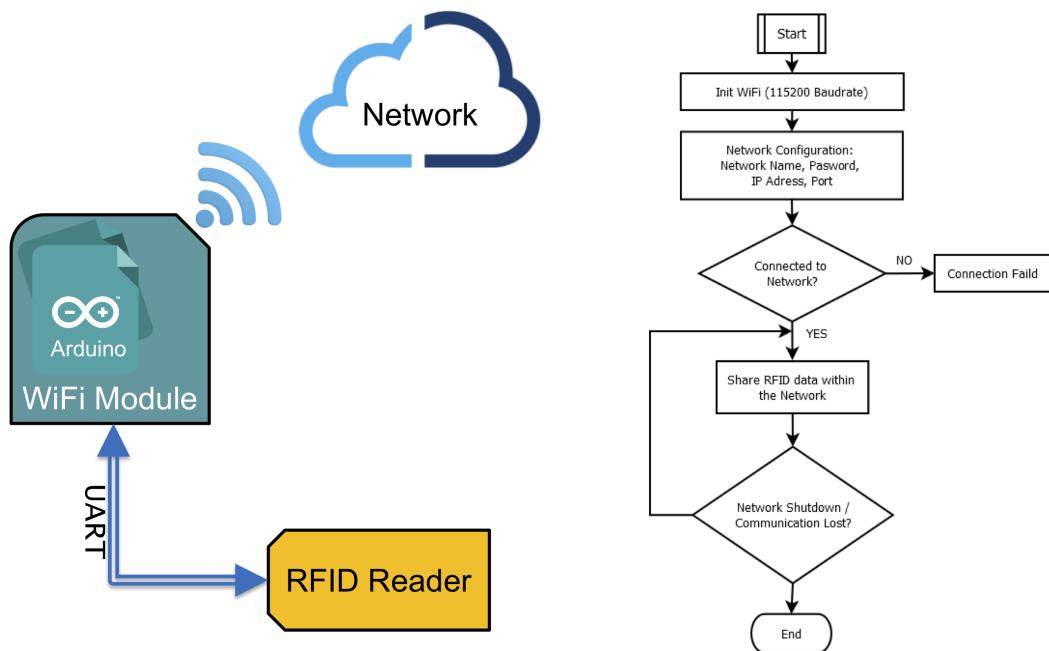


Figure 30: WeMos Module Network Communication

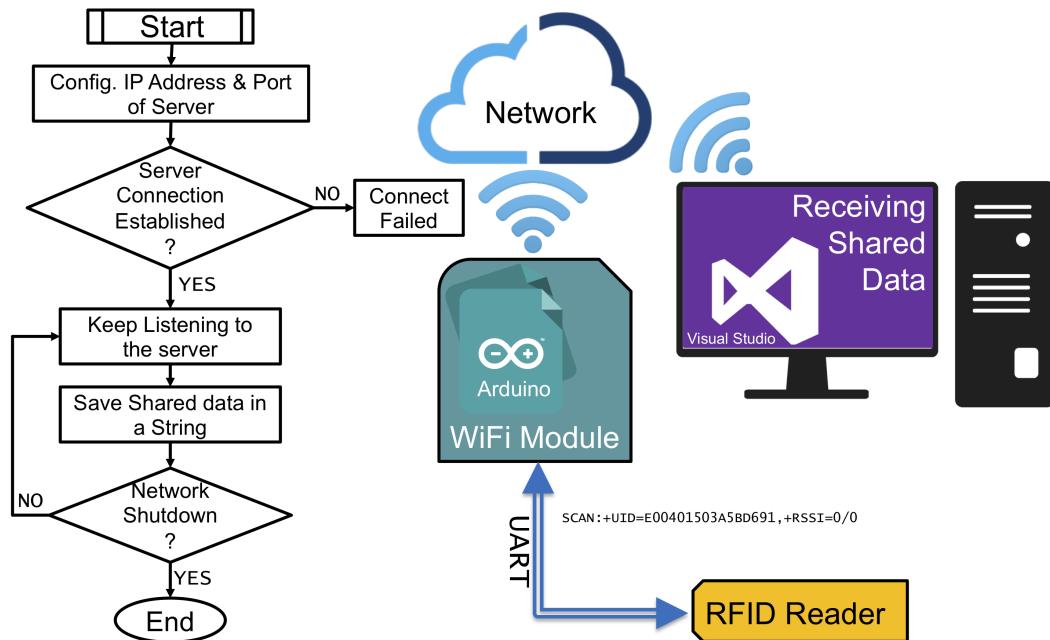


Figure 31: Computer Network Communication

7.2 Initialization procedure

In the start-up phase, before running the pipeless plant with its AGVs the correct position and orientation of each and every vehicle are not known. Even though the controller is able to compute the position of the AGVs antenna in each point of time ($t=0$ included), several AGV positions in the plants operation space can be described by one single antenna position. In fig. 32 four possible AGV positions with one common antenna position are pointed out.

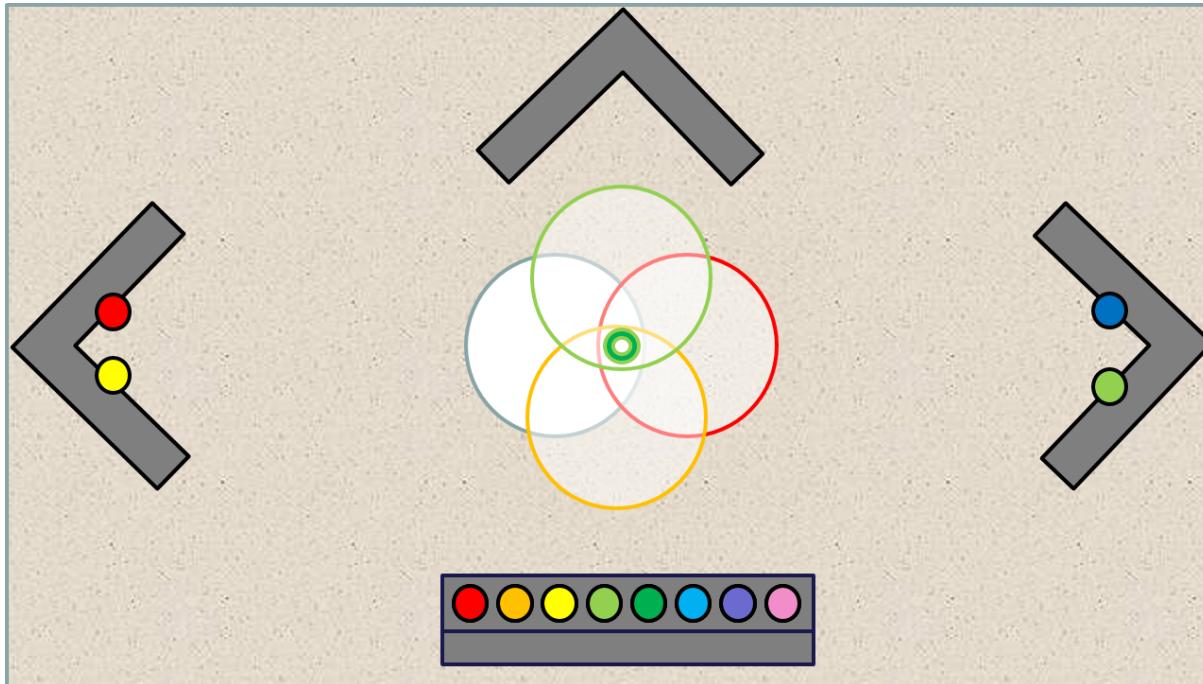


Figure 32: Different possible positions for one antenna position

Since the position information is crucial for the plant, a procedure was set up to determine the starting positions of each and every AGV. According to the fact, that the position and orientation of a single AGV is unknown at the beginning, some potential are taken into account. For instance, the plant contains several obstacles like the mixing stations, vessel storage, charging stations, plant edges and even other vehicles as represented in fig. 33.

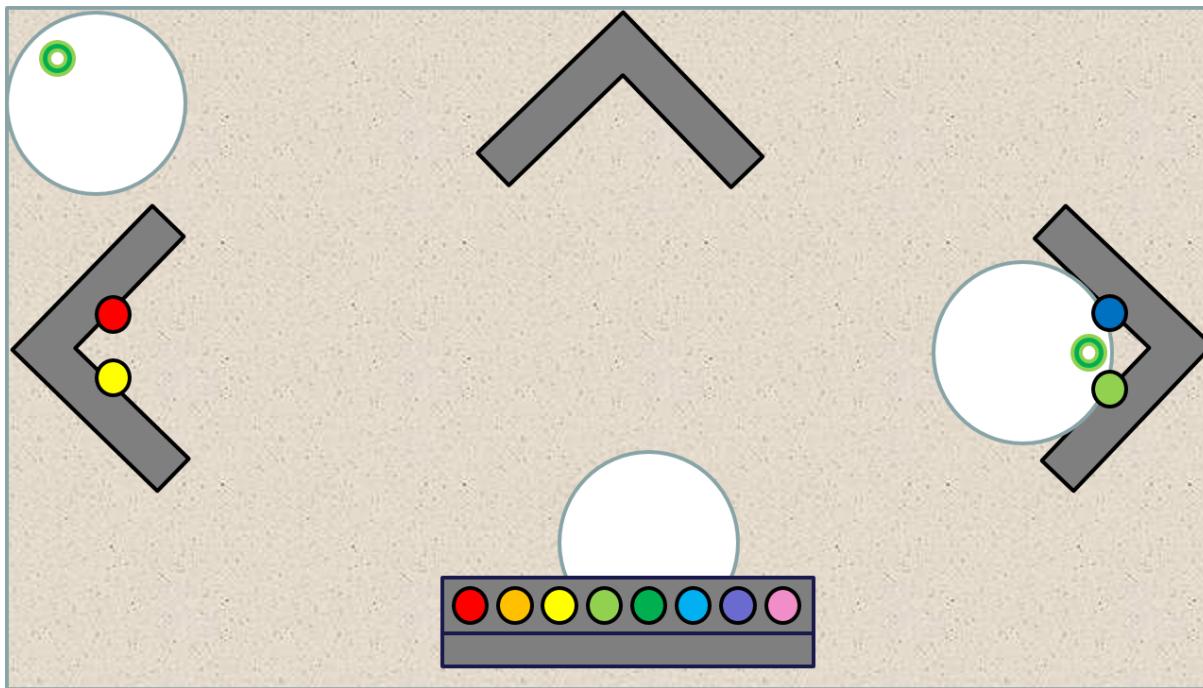


Figure 33: Possible hazards/obstacles

With respect to these potential hazards collisions during the initialization procedure have to be avoided. This is realized by taking advantage out of the AGVs ability to turn around its z axis without a change of the AGVs center point in x and y direction. This ability of the AGV leads the way that each and every robot performs an initialization turn of 360° in which measurements are taken every 45° to estimate the specific positions and orientations of the AGVs. Furthermore, the decision process of the antenna position under the robot is dominated by the fact that the position of the center point does not change during a turn around its z axis. During the 360° turn the intervals in which the measurements have to be taken need to be known by the controller. The determination of these measurement points can be computed in two different ways. On the one hand the encoders of the AGV-wheels can be used to estimate the performed rotation. On the other hand, the time of a complete turn can be measured and used as a parameter in the procedure. In terms of simplicity the second option is used in the initialization procedure. Fig. 34 illustrates a sequential flow chart which describes the movement and data processing during the initialization procedure. The part of the code which is explained and visualized by Fig. 34 is found in section 11.4

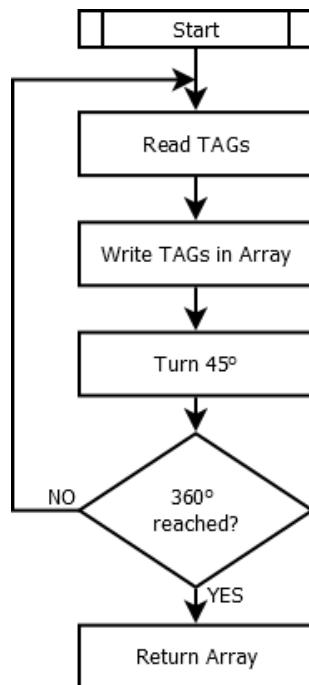


Figure 34: Flow Chart: Initial procedure 360° turn

The initialization procedure for AGV No. 1 is created and can be started in the GUI in the test environment. In the first place an integer number is given to the field called SleepTime. This integer number is interpreted in milliseconds and describes the time of rotation. Even though a time for a complete turn of 45° has been found at around 1125ms it has to be said that this time strongly depends on the battery charge of the AGV. After the desired turning time is given to the GUI the initialization is started by pushing the button Initialization, located over the input box in fig. 35.

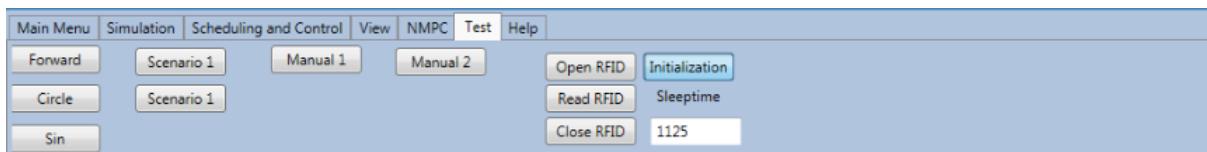


Figure 35: Test environment in GUI

In the second step, after the procedure was started, all the available IDs and their respective

RSSI in the current reading range of the RFID-Reader are read. The reading is performed in the Automatic Scan mode of the RFID reader[12]. With the included timestamp for every measurement a delay of minimum 30ms between each tag information was detected. With respect to this delay the antenna has to stop a specific period of time at each measuring point to deliver correct data of all the reachable tags. Experiences have shown, that a measuring time between one and two seconds delivers the best results. During this time every 100 ms new measurement information are taken. In order to save the single TAG information of each and every measuring point an initially empty array with 14 columns and 8 rows is created. The number of rows is derived by the fact that measurements are taken at every 45° .

$$Rows = 360^\circ / 45^\circ = 8 \quad (12)$$

(13)

The first seven columns in the array are filled by the received TAG IDs and the last seven entries are filed by the respective RSSI.

The number of columns is derived by the fact that at each and every measurement point in the used test environment, information of maximal seven TAGs can be read.

$$Columns = max.no.oftags * 2 = 7 * 2 = 14 \quad (14)$$

(15)

Once the received data is saved in its corresponding row, the AGV turns around 45° to place the antenna at the next measuring point. An AGV turn is realized by setting the velocity of the right and left wheel in different directions. During the turning sections the velocity is set to 100 mm/s or rather -100 mm/s. This procedure of reading information, writing information in the initialization array and turning 45° to the next measuring point is repeating itself until a 360° turn is performed. After a successful initialization turn the corresponding array of measurement information can look like the example in table 10. The code which realizes the filling of the array can be seen in section 11.5

4	1	5	2	3			0	0	1	7	0		
5	3						2	3					
3	5						2	2					
9	8	6	5				1	1	1	2			
9	7	8	6	4	5		2	0	6	0	0	2	
4	7	5	8				0	2	3	3			
5	4	7	8	1			2	5	0	0	0		
2	4	1	5				0	2	2	0			

Table 10: Filled array after 360° turn

7.2.1 Recording and filtering data

To read the ID and RSSI of all the TAG laying in the reading range the RFID-reader is set to its Automatic mode and its Anticollision is switched on. In this mode packages of strings with a length of 35 characters are received by the plans computer. Even though these 36 character strings contain all the information of the TAG which is needed some effort has to be taken to seperate the useful parts which are processed in the localization algorithm.

With exception of the information each string contains, the structure itself is always the same. In the first five characters the substring “SCAN:” is detected and deleted for the further process. The first important character is found in the sixth slot of the string. Here either a “+” or a “-” is written. With the help of this sixth slot it is distinguished wheather the current reading is complete or not. In order to guarantee the correctness of the received information the measurments are filtered by the “+” and the measurments in which a “-” is included are ignored in the further processes. After the indicator for complete and in complete readings a introduction to the ID is indicated by “UID= ” and cut out of the string. The next 16 characters defines the unique identification of the specific TAG. As a last useless string, which has to be cut out, with the structure “.RSSI=” is found directly after the ID. As a result the 16 character hexadecimal ID and its respective RSSI are seperated from the received string. Since the ordered tag IDs differ each other just in the last three numbers these numbers are transformed in a decimal number before UID and RSSI are used for further computations. The code which realizes the recording and filtering of the data can be seen in section 11.2

String Transformation	
Complete	Incomplete
SCAN:+UID=E00401503A5BD691,+RSSI=0/0	SCAN:-UID=E00401503A5BDAE4
UID=E00401503A5BD691,+RSSI=0/0	
E00401503A5BD691 0/0	
1681 0	

Table 11: String preperation

7.2.2 Analysing data

In the next step of the algorithm the previous described filled array is analyzed. To estimate the position and orientation of the AGV the array has to include two valid sets of each two valid measuring points. During this analyzation the single measurement point-sets are validated in terms of following restrictions:

- 1.: At the two valid measurement point each contains at least three tags
- 2.: The other measurement point in one set needs to have a distance of 180° to the first.

In terms to get the adequate sets of measurement points the array is analyzed row by row. The stepwise workflow is visualized in fig. 36.

The code in which the analysis is realized can be seen in section 11.6

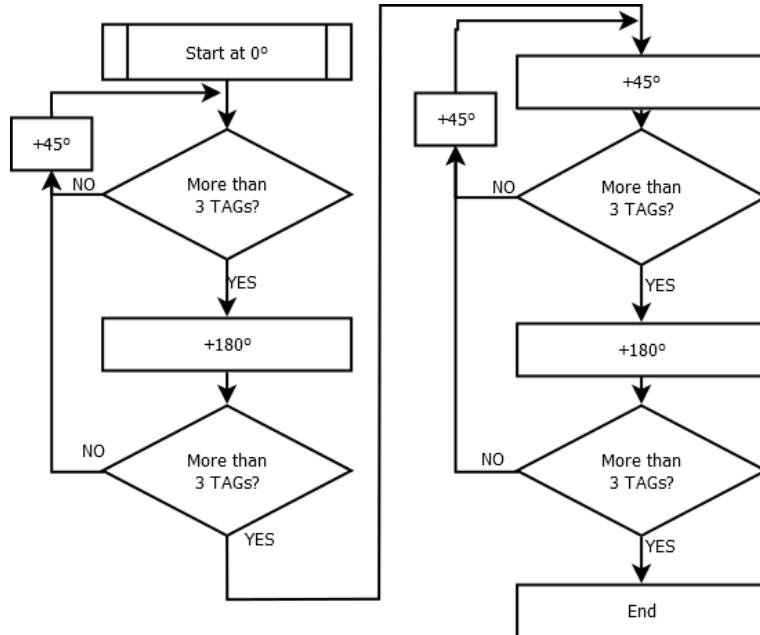


Figure 36: Flow Chart: Analizing measurement points

Initially the first row which represents the measurement at the point 0° is checked in terms of the number of readable tags. If this specific number is higher or equal three the transition is acknowledged as true and the same query will be performed at the measurement point with a distance of 180° to the former measurement point. If this next measurement point can be described as valid, the first valid set of two measurement points is found. If, on the other hand, the number of readable TAGs are less than three, which means that the triangulation algorithm cannot be performed, the current measurement point is ignored and the next measurement point is evaluated. Each of this sets of two measurement points is saved as a 1×2 array called Solution 1 and Solution 2 is used for the estimation of the position of the measurement points which is explained in the section 7.2.4 Estimation of initial position and orientation.

7.2.3 Selection of correct distance related to RSSI⁶

In a first step the multiple occurring data points (see tbl.8) are divided into three groups (max, middle and min) where max means the maximal possible distance related to one RSSI and so on.

⁶Stephan

The measurements have shown that it is not trivial to define the correct distance related to most of the RSSI. The involved algorithm selects the correct distance out of the multiple possible solutions and is shown in fig. 37:

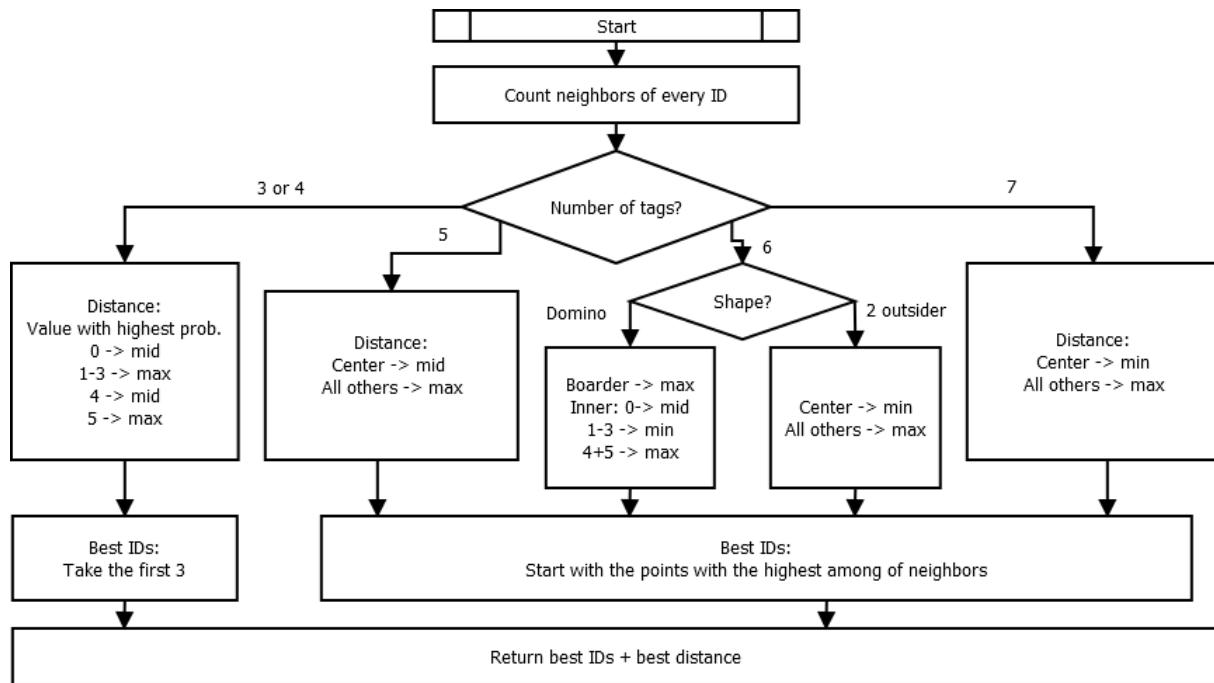


Figure 37: Flow Chart: Selection of correct distance and most proper IDs

To distinguish between the multiple possible solution for one RSSI, the algorithm defines the shape of the pattern of tags based on the number of tags at each measurement and the number of the neighbours each tag has. At each measurement point in this scenario several numbers (4-7) of detected tags are possible. The different shapes can be found in thetbl. 12.

Number of detected tags	4	5	6 (Domino)	6 (2 alone)	7
Unique shapes					

Table 12: Possible shapes of pattern

Going back to the flow chart fig.37 the first step is to count the number of neighbours each tag has. With this information, the position of the tag in the pattern can be detected. For example, a tag with 3 neighbours in a pattern of 5 tags, is the center of this pattern.

After the number of tags at each measurement point and the position of each tag are defined, the selection of the correct distance will be performed based on the highest probability. To know the highest probabilities an analysis of measurements with emulated data has been done.

As an example 4 detected tags are leading to the fact that the position of the antenna should be very close to the center of this square. If in this case a RSSI of 4 is detected, the middle value (5.8 cm) will be taken.

Afterwards the most suitable three IDs will be selected, in case where more than three are detected. The algorithm takes at first the ID with the highest amount of neighbours, because these tags are close to the position of the antenna and have probably a value of 6 or 7 and are uniquely defined. In the case where several tags with the same number of neighbours, the first ID (number increasing) will be taken.

The return of the function is an array (2x3) with the indices of the chosen IDs and the correct distance. The correct distance will be indicated by the number 0,1 and 2. 0 means the maximal, 1 the middle and 2 the minimum possible value related to one RSSI. For example

$$\begin{bmatrix} 3 & 2 & 4 \\ 2 & 0 & 0 \end{bmatrix}$$

leads to the choice of the maximal value of the RSSI of the fourth detected ID and the minimum value of the RSSI of the third and the fifth ID in the recorded array at this measurement point.

7.2.4 Estimation of initial position and orientation ⁷

As mentioned in chapter ??, the main idea to estimate the initial position is to find the intersection point, which lies in the middle of the measurement points.

To compute this position, the algorithm uses trilateration at every suitable measurement point to estimate its position. For trilateration are three defined positions plus three radii necessary, which are available after the selection of the correct distance and proper IDs.

As follows from the fig.38 shown above, the intersection point is found by computing two linear functions which go through two corresponding points (blue lines). The center of the robot is then the intersection of those two linear functions and can be computed by the following equations:

$$x = \frac{(x_1y_2 - y_1x_2)(x_3 - x_4) - (x_1 - x_2)(x_3y_4 - y_3x_4)}{(x_1 - x_2)(y_3 - y_4) - (y_1 - y_2)(x_3 - x_4)} \quad (16)$$

$$y = \frac{(x_1y_2 - y_1x_2)(y_3 - y_4) - (y_1 - y_2)(x_3y_4 - y_3x_4)}{(x_1 - x_2)(y_3 - y_4) - (y_1 - y_2)(x_3 - x_4)} \quad (17)$$

Theoretically all eight measuring points are suitable points (at least four IDs found). But for the case that the real measurements differ from the theory, the algorithm just needs four suitable

⁷Stephan

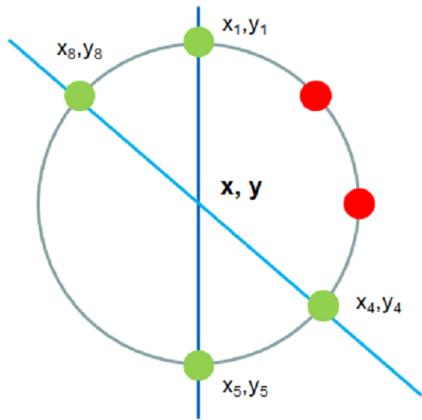


Figure 38: Computing the center of the robot

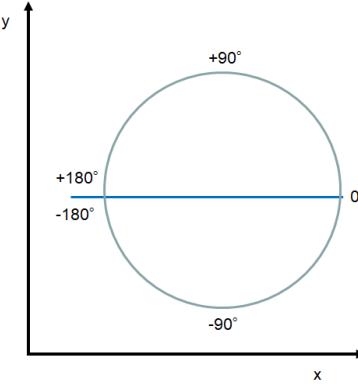


Figure 39: Orientation of robot in absolute angle

points.

After the initial position as well as the positions of 4 measurement points are known, the algorithm computes the orientation based on those information. The relative angle between the center and the first measurement point will be computed with the arctan2 function and leads to an orientation $-180^\circ < \Theta \leq 180^\circ$ as shown in fig.39.

To compute the absolute angle, the angle of the measurement point has to be subtracted and 180° has to be added. This is caused by the fact that the antenna is placed on the back of the robot and the absolute orientation should be the direction of the front. After this computation, the initial position and orientation of the robot are known.

7.3 Test setup⁸

In order to verify the validity of the initialization procedure, experiments with the components mentioned in chapter 5 were carried out. The beginning of these experiments were the reconstruction of one of the AGVs with this HW setup. After all components were added to the AGV the power supply was realized via a powerbank and the USB connection of then wifi modul. The plan is to replace this in the future with a direct connection to the battery of the AGV. Fig.40 gives an overview of the test setup and shows that also for the prototype, the reader and the wifi modul was just stuck with Sellotape on the upper layer of the AGV.

The test platform was a field of 9 tags which were stuck on a piece of carton. The IDs and its positions are shown in tbl.13.

The reason for the small setup was the fact that until the end of the project only 10 tags were available. One of the following steps should be to extend the platform with more tags.

⁸Stephan

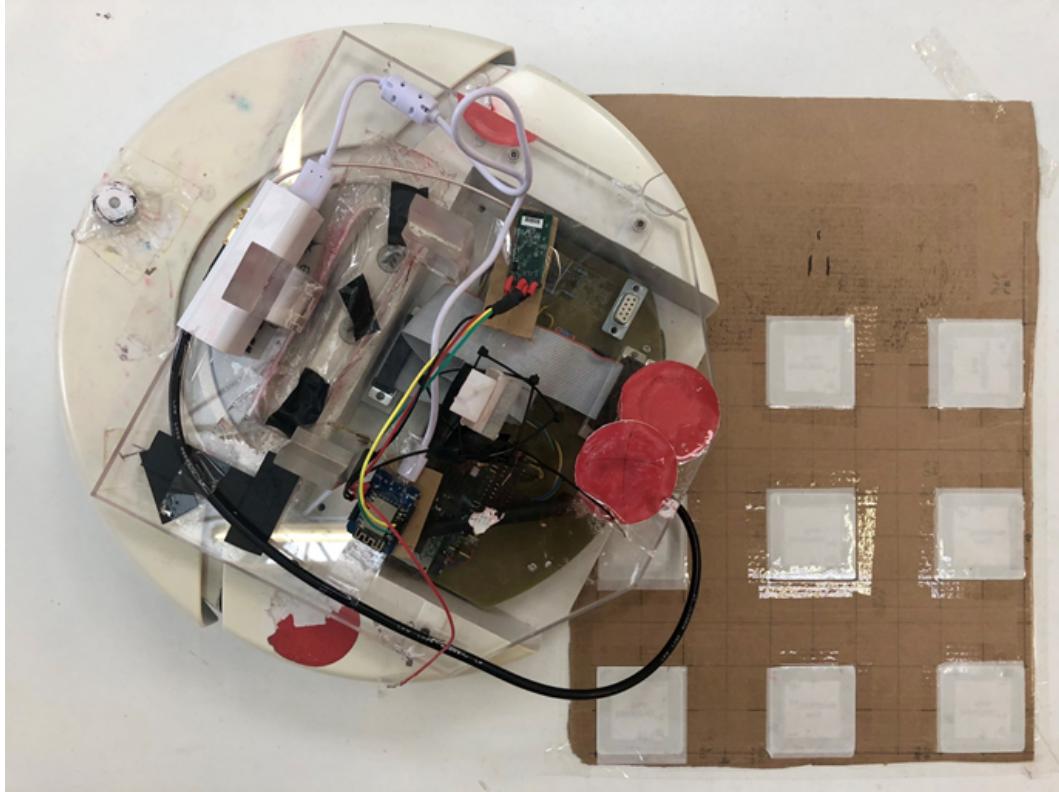


Figure 40: testing setup for initialization procedure

X-dir. [mm]	0	100	200	0	100	200	0	100	200
Y-dir. [mm]	0	0	0	100	100	100	200	200	200
ID tag [hex]	AE4	689	47A	586	785	ADC	BF4	691	78D
ID tag [dec]	2788	1673	1146	1414	1925	2780	3060	1681	1933

Table 13: Positions of the IDs in the test setup

The initialization procedure was started via the GUI. A time value was added in the GUI to perform the 45° turns. This number was around 1125 ms and is highly correlated to the battery status of the AGV.

7.4 Results⁹

A couple of tests on the test setup (previous section) were performed to compare the good results created with the simulated data with real measurements. The result of the position estimation was directly plotted in the console. The initial position was 200 mm in x- and y-direction and a varying orientation (0° , 90° , 180° and -90°). Fig.41 and fig.42 illustrate the actual measurement results and the desired position in x- and y-direction.

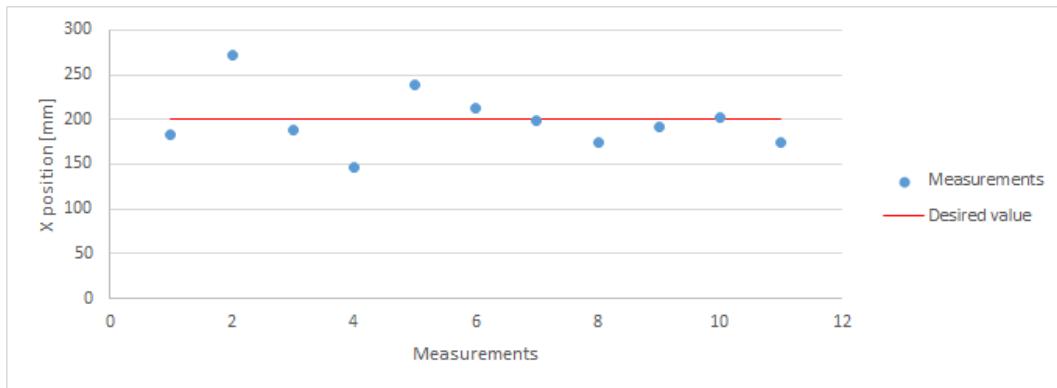


Figure 41: Estimated position in x-direction

The average of the absolute error of the position in x-direction was 24.5 mm. The minimum and maximum error were 2 mm and 72 mm.

The average of the absolute error of the estimation of the position in y-direction is with 23.3 mm, a minimum error of 3 mm and an maximum error of 77 mm very similar to the results from the estimation of the x-direction. The computation of the overall error of the position has an average derivation of 37.5 mm and a minimum and maximum error of 6.3 mm and 77 mm.

For the estimation of the orientation, the average of the absolute error was 23° with a minimum and a maximum value of 3.9° and 37.5° . The measurements also shows that an estimation of the position with a big error not necessarily leads to a big error in the estimation of the orientation (see measurement 4 in fig.41, 42 and 43).

An extension of the results could also be an analyse of the estimated positions of the antenna at the measurement points. Those points were also plotted in the console.

⁹Stephan

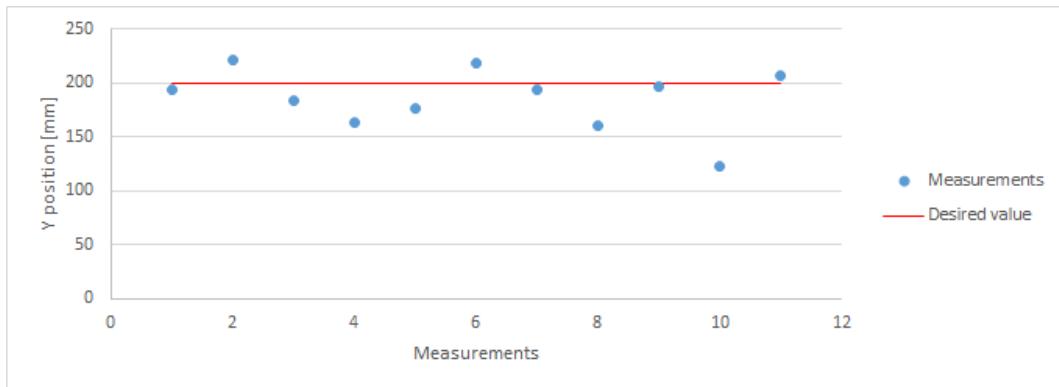


Figure 42: Estimated position in y-direction

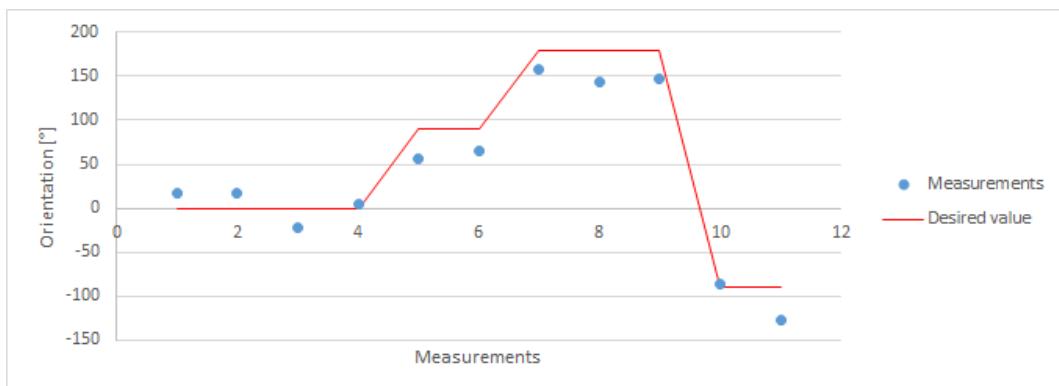


Figure 43: Estimated orientation

8 Conclusion

The developed localization solution was for the pipeless plant, a prototype of a chemical production plant which has a size of 3 by 4 meter. In this plant the vessel will be transported by AGVs from one station to another. In the actual setup only a camera, which is installed above the plant, was used to detect the AGVs and estimate their positions. The problem with this technology is the bad detection of the LED pattern from the AGVs during bright light conditions and also the space limitation. Another big disadvantage was the big computation effort which made the system also very slow. The main task of this project was to find an alternative tracking solution. During the project group phase different localization technologies were evaluated. With respect to the outcome researches about triangulation, map-based-localization, pattern recognition and localization via radio frequency identification the last RFID based localization of the AGV with passive tags as landmarks turned out to be the most promising among those four. With information of a similar project realized by the FH Dortmund a model to evaluate sample data and a localization algorithm was created in Matlab. The results of the simulation were promising and therefore used during the decision making process about the actual hardware setup. With a demonstration board with the size of 30 cm x 30 cm the initialization procedure algorithm was implemented in which the AGV performs a 360° turn and estimates its position and its orientation based on measurements during this movement. With respect to this solution it can be said that it is possible to assemble a reader on an AGV and detect passive tags with its antenna in a range of 14 cm. It also has been found out that an inconsistent realization between the reviewed signal strength (RSSI) of the detected TAGs and the distance based on the RSSI is not generally trivial and was only solved in a rather simple and unreliable way during the project. Based on the results computed by the initialization procedure, it can be concluded that it is possible to estimate the position of the AGV with an average accuracy of around 2.5 cm and an estimation error of the orientation of around 23°. Compared to the former localization set up this solutions, especially with respect to the orientation error, are not perfectly satisfying and just minimal requirements are fulfilled. The received data from the RFID reader have furthermore clearly shown that the anti-collision algorithm used by the reader leads to an unknown amount of time until each and every TAG in the detection area is identified. Summed up a model based demonstrator was realized which on the one hand does not improve the accuracy of the localization of the plant under good light conditions especially with respect to the orientation but on the other hand a promising technology for indoor localization with light independence, respectively cheap costs and highly scalability was found.

9 Future work

After a proof-of-concept for an RFID based localization system has been built and a first demonstration set-up has been built the disadvantages and limitations of the prototype were evaluated. According to these results several points of improvement and extension were found and categorized into a hardware and a software section.

9.1 Hardware

- The AGVs are feed by an included 12V battery which provides the power for all included electronical devices. This 12V power supply is available on board and is suggested to be used. Currently the WiFi-Module and the RFID-Reader are fed by an external powerbank since a 5V power supply is needed. In terms of one zentralized power supply a 12 V to 5 V converter can be installed and connected to the reader and wifi module.
- As a first setup a demonstration area of 3 x 3 tags was build. In this rather small area the initializaion procedure was developed, but a real time localization while a path is followed by an AGV was not possible since the 30cm x 30cm was simply to small. For futrue research in terms of localizaion on a specified path additional TAGs can be included to the area of operation. Since the RFID concept is highly scalable the only change that needs to be made in the algorithm is the insertion of the additional TAG into the lookup table.
- Currently the Robot No. 1 is the only AGV which is equipped with the RFID technology. To run the plant with multible AGVs the remaining robots needs to be upgraded.

9.2 Software

- During the initalizatin procedure a 360° turn is performed. The desired turn around 45° is realized by a driving time of 1125 ms. But it needs to be said that this movement is highly dependend on disturbances like changing battery charge and plant underground. For the future developers it is suggested to use the encoders of the robot wheels as a determination of the orientation instead of the parameter time.
- As an alternative localization technology was found several code lines in the current code can be deleted since the camera and image processing is simply not used anymore. With a clean code an improvement of processing time will be achieved.
- As a last point it can be said that even though a localization with RFID is now possible the results are not 100 percent realiable and the accuracy especially with respect to the orientation is not satisfying so far. As an improvement the triangulation algorithm has to be optimized and or a second RFID-antenna has to be added under the AGV to reduce measurment errors.

10 References

References

- [1] Yihuan Zhang Liang Wang and Jun Wang. Map-based localization method for autonomous vehicles using 3d-lidar. *IFAC (International Federation of Automatic Control) Hosting by Elsevier*, 50, 2017.
- [2] Dr.-Ing. habil. Dipl.-Ing. Dipl.-Ing. Joerg Wollnack. Prinzip der dreidimensional messenden videometrischen messsysteme.
- [3] Jeremie Houssineau, Daniel Clark, Spela Ivezkovic, Chee Sing Lee and Jose Franco. A unified approach for multi-object triangulation, tracking and camera calibration.
- [4] Matteo Munaro, Edmond Wai Yan So, Stefano Tonello, and Emanuele Menegatti. Efficient completeness inspection using real-time 3d color reconstruction with a dual-laser triangulation system. 48:201–225, 09 2015.
- [5] F. Dias, H. Schafer, L. Natal, and C. Cardeira. Mobile robot localisation for indoor environments based on ceiling pattern recognition. In *2015 IEEE International Conference on Autonomous Robot Systems and Competitions*, pages 65–70, 2015.
- [6] Yuntian Brian Bai, Suqin Wu, Hongren Wu, and Kefei Zhang. Overview of rfid-based indoor positioning technology, 2012.
- [7] Jun Liu Baoxian Zhang and Haoyao Chen. Amcl based map fusion for multi-robot slam with heterogenous. *IEEE International Conference on Information and Automation (ICIA)*, 6, 2013.
- [8] ROS. Amcl, 2018.
- [9] Hanifa SHAH Kamran AHSAN and Paul KINGSTON. Rfid applications: An introductory and exploratory study. *International Journal of Computer Science Issues*, 7(3), 2010.
- [10] Vinita Sharma Ms.Neha Kamda and Sudhanshu Nayak. A survey paper on rfid technology, its applications and classification of security/privacy attacks and solutions. *IRACST - International Journal of Computer Science and Information Technology & Security*, 6(4), 2016.
- [11] Pablo Cotera, Miguel Velazquez, David Cruz, Luis Medina, and Manuel Bandala. Indoor robot positioning using an enhanced trilateration algorithm. *International Journal of Advanced Robotic Systems*, 13(3):110, 2016.
- [12] KTS Systeme. Rfid plug module rfidm1356, 2017.
- [13] WEMOS. Wemos d1 mini, 2018.

- [14] Christof Rohrig, Daniel Hess, and Frank Kunemund. Rfid-based localization of mobile robots rfid-based localization of mobile robots using the received signal strength indicator of detected tags.

11 Appendixes

11.1 Appendix A: Emulator RFID data (Matlab)

```

1 %% _____
2 % Description: Emulator, which creates txt file like the reader
3 %               RSSI related to the real measurements
4 %               For the Initialization procedure, turn around 360°
5 % Date:        12.06.2018
6 % Created by: Stephan Vette
7 %
8 %% RFID signal emulator
9 clear all
10 clc
11 close all
12 % Initializing
13 l1 = 100;    % length of the plant, x [cm]
14 l2 = 11;     % width of the plant, y [cm]
15 d1 = 10;     % distance between tags [cm]
16 d2 = 0;      % distance last tag <-> boarder [cm]
17 r1 = 14;     % radius of the reading range of every tag
18 r2 = [r1, 9.75, 9.0, 8.0, 7.0, 6.0, 5.8, 5.5, 5.3, 5.1, 5.0, 4.7, 4.5, 4.3, 4.2, 4.0,
       3.5, 2.75, 0]; % distances at certain RSSI
19 r4 = [0, 1, 2, 3, 4, 5, 4, 3, 2, 1, 0, 1, 2, 3, 4, 5, 6, 7, 7]; % array with the
                     different RSSI values
20
21 r3 = 33/2; % radius of the robot
22 d3 = 10;    % distance between origin robot and origin antenna [cm]
23
24 angle1 = 45; % angle between the measurement points in the init procedure
25
26 gammal = deg2rad(22.5); % Start orientation of robot [rad]
27 robStart = [22.5, 51.5]; % Start position of robot in x, y [cm]
28
29 robSpeed = 0.1;        % Speed robot [m/s]
30 cycleT = 100;          % Cycletime in [ms]
31
32 mode = 1;   % mode=1: tracking all available tags, which are nonzero
            % mode=2: tracking only changes in the RSSI signals
33 mode_hex = 0; % activate or deactivate hex ID
34
35 % For the name of the txt file
36 measuementeNumber = num2str(11); % Number of measurement
37 % Two possibilities for the content of the txt file
38 % 1. Without filtering. Exactly like the reader creates data
39 % text0 = '<\r>';
40 % text1 = 'OK';
41 % text2 = 'SCAN:+UID=';
42 % text3 = '+RSSI=';
43
44 % 2. Filtered data. Without unusable information.
45 text0 = ',';
46 text1 = ',';
47 text2 = ',';
48 text3 = ',';
49
50 %% Error check
51 if mod(11/d1,1)~=0
52     error('Length of platform not dividable by distance between tags');
53 elseif mod(12/d1,1)~=0

```

```

54     error('Length of platform not dividable by distance between tags');
55 end
56
57 %% Computing position of antenna
58 numTagsX = (l1-2*d2)/d1 +1;
59 numTagsY = (l2-2*d2)/d1 +1;
60 numTags = numTagsX * numTagsY;
61 antPos = robStart + d3 * [cos(gamma1), sin(gamma1)];
62
63 %% Display the setup, write important information into a seperate txt file
64 d1_str = num2str(d1);
65 l1_str = num2str(l1);
66 l2_str = num2str(l2);
67 numTags_str = num2str(numTags);
68
69 msg0 = ['Your plane is ',l1_str,'cm x ',l2_str,'cm.'];
70 msg1 = ['You chose a distance of ',d1_str,'cm and need ', numTags_str, ' Tags!'];
71 disp(msg0);
72 disp(msg1);
73 nameTxt = ['NumTags',measuementeNumber,'.txt'];
74 fileNumTags = fopen(nameTxt,'w');
75 fprintf(fileNumTags,'%6d\n',numTags); % Write the number of tags in file
76 fprintf(fileNumTags,'%6d\n',l1); % Write the size of the plant in file
77 fprintf(fileNumTags,'%6.4f\n',gamma1); % Write the starting angle
78 fprintf(fileNumTags,'%6d\n',robStart(1)); % Write the starting pos
79 fprintf(fileNumTags,'%6d\n',robStart(2)); % Write the starting pos
80 fclose(fileNumTags);
81
82
83 %% Drawing environment
84 figure(1)
85 x1 = [0 l1 l1 0 0];
86 y1 = [0 0 l2 l2 0];
87 plot(x1, y1, 'LineWidth',2)
88 xlim([-5 (l1+5)]);
89 ylim([-5 (l2+5)]);
90 hold on
91
92 % Position of the tags
93 ID = 1:numTags;
94 [Tagx,Tagy] = meshgrid(d2:d1:l1-d2,d2:d1:l2-d2);
95 plot(Tagx,Tagy,'r*')
96 % Circles
97 radiipl = ones(numTagsX,1)*r1;
98 for k=1:numTagsX
99     tempx = Tagx(1:end,k);
100    tempy = Tagy(1:end,k);
101    temppos = horzcat(tempx,tempy);
102    viscircles(temppos,radiipl,'Color','k','LineStyle',':','LineWidth',0.25);
103 end
104 robX = robStart(1);
105 robY = robStart(2);
106 plot(robX,robY,'bO','LineWidth',3);
107 plot(robX,robY,'r:');
108 viscircles([robX,robY],r3,'Color','k','LineWidth',0.25);
109 plot(antPos(1),antPos(2),'bs');
110 xlabel('Length platform in cm')
111 ylabel('Width platform in cm')
112 title({'Position and reading range of tags';'Start-, endpoint and path of the robot'}));

```

```

113 hold off
114 pause(1)
115
116 % Animation and loggin
117 xUpdateAnt = antPos(1);
118 yUpdateAnt = antPos(2);
119 deltaR = deg2rad(angle1); % A new measurement after every XX°
120 % Txt file name
121 name = ['Meas_StartingProc_like_reader_real_data',measuementeNumber,'.txt'];
122 fileID = fopen(name, 'w');
123
124 % Data stored in variables
125 dataRSSI = zeros(8,numTags);
126 streamDataRSSI = zeros(1,numTags);
127 streamDataRSSIold = zeros(1,numTags);
128 timeStep = 1; % current measurement step
129
130 % antPos = robStart + d3 * [cos(gamma1), sin(gamma1)];
131 figure(2)
132 for l=0:360/angle1
133     deltaR_temp = deltaR * l;
134     xUpdateAnt = robStart(1) + d3 * cos(gamma1 + deltaR_temp);
135     yUpdateAnt = robStart(2) + d3 * sin(gamma1 + deltaR_temp);
136     plot(x1, y1, 'LineWidth',2)
137     hold on
138     xlim([-5 (11+5)]);
139     ylim([-5 (12+5)]);
140     [Tagx, Tagy] = meshgrid(d2:d1:l1-d2, d2:d1:l2-d2);
141     plot(Tagx, Tagy, 'r*')
142     plot(robX, robY, 'bO', 'LineWidth',1);
143     plot(robX, robY, 'r:');
144     plot(xUpdateAnt, yUpdateAnt, 'bs');
145     xlim([-5 (11+5)]);
146     ylim([-5 (12+5)]);
147     viscircles([robX, robY], r3, 'Color', 'b', 'LineWidth', 0.5);
148     for k=1:numTagsX
149         tempx = Tagx(1:end,k);
150         tempy = Tagy(1:end,k);
151         temppos = horzcat(tempx, tempy);
152         viscircles(temppos, radiipl, 'Color', 'k', 'LineStyle', ':', 'LineWidth', 0.25);
153     end
154 hold off
155
156 % Creating measurements
157 antPosnew=[xUpdateAnt,yUpdateAnt];
158 for m = 1:numTags % m = current number of tag
159     m_str = num2str(m);
160     tempTag=[Tagx(m),Tagy(m)];
161     tempD = pdist([antPosnew; tempTag], 'euclidean');
162
163 % Display if tag is in range or not
164 if tempD > r1
165     streamDataRSSI(m) = 0;
166     if (streamDataRSSI(m) ~= streamDataRSSIold(m)) && mode == 2
167         if mode_hex == 1
168             fprintf(fileID, '%d %s%s%s%d%s\n', l*angle1, text2, dec2hex(m, 16),
169                     text3, k(end), text0);
170         elseif mode_hex == 0
171             fprintf(fileID, '%d %s%d%s%d%s\n', l*angle1, text2, m, text3, k(end),
172                     text4);
173     end
174 end

```

```

171         text0);
172     end
173     fprintf(' %d %d %ld\n',l*angle1,m,'0');
174   end
175 elseif tempD <= r1
176 % disp(['Label ',m_str,' in range !!!!!!!! ']);
177 % Relation distance <-> RSSI
178 k_temp = find(r2>=tempD);
179 k = r4(k_temp);
180 dataRSSI(timeStep,m) = k(end);
181 streamDataRSSI(m) = k(end);
182 if (streamDataRSSI(m) ~= streamDataRSSIold(m)) && mode == 2
183   if mode_hex == 1
184     fprintf(fileID , '%d %s%s%s%d%s\n' ,l*angle1 ,text2 ,dec2hex(m, 16) ,
185             text3 ,k(end) ,text0);
186   elseif mode_hex == 0
187     fprintf(fileID , '%d %s%d%s%d%s\n' ,l*angle1 ,text2 ,m ,text3 ,k(end) ,
188             text0);
189   end
190   fprintf(' %d %d %8d,\n',l*angle1 ,m ,k(end));
191 elseif mode == 1
192   if mode_hex == 1
193     fprintf(fileID , '%d %s%s%s%d%s\n' ,l*angle1 ,text2 ,dec2hex(m, 16) ,
194             text3 ,k(end) ,text0);
195   elseif mode_hex == 0
196     fprintf(fileID , '%d %s%d%s%d%s\n' ,l*angle1 ,text2 ,m ,text3 ,k(end) ,
197             text0);
198   end
199   fprintf(' %d %d %ld,\n',l*angle1 ,m ,k(end));
200 end
201 end
202 streamDataRSSIold = streamDataRSSI;
203 pause(cycleT/1000)
204 timeStep = timeStep + 1;
205 end
206 savefig('Figure2.fig');
207 fclose(fileID);
208 %% Results
209 % figure(3) % plot for the max value of every tag
210 % dataRSSInoT = reshape(max(dataRSSI),[numTagsX,numTagsY]);
211 % plot3(Tagx,Tagy,dataRSSInoT,'*');
212 % xlabel('Length platform in cm')
213 % ylabel('Width platform in cm')
214 % title('Max RSSI signal of every tag')
215
216 figure(4) % plot of the RSSI signal which are non zero vs. time
217 dataRSSIsum = sum(dataRSSI);
218 IDclear = find(dataRSSIsum ~= 0);
219 IDstr = string(IDclear);
220 dataRSSIClear = dataRSSI;
221 dataRSSIClear( : , all(~any(dataRSSI), 1) ) = []; % and columns
222 plot(dataRSSIClear);
223 xlabel('Measurement points')
224 ylabel('RSSI')
225 ylim([0 360/angle1])
226 legend(IDstr,'FontSize',6);
227 title('RSSI Signal of every non zero tag')

```

11.2 Appendix B: Receiving data from reader via Wifi (C#)

```
1  using System;
2  using System.Collections.Generic;
3  using System.Linq;
4  using System.Text;
5  using System.Windows;
6  using System.IO;
7  using System.Threading;
8  using System.Net;
9  using System.Net.Sockets;
10 using MULTIFORM_PCS.ControlModules.SchedulingModule;
11 using MULTIFORM_PCS.ControlModules.FeedForwadModule;
12 using MULTIFORM_PCS.ControlModules.RoutingModule.PathAndVelocityPlanning.
     DataTypes;
13 using MULTIFORM_PCS.ControlModules.CameraModule.CameraForm;
14 using MULTIFORM_PCS.ControlModules.CameraControl.CameraControlClass;
15 using System.Windows.Threading;
16 using System.Diagnostics; // Process
17 using System.Globalization;
18 using Emgu.CV.WPF;
19 using System.Threading.Tasks;
20 using System.Collections.Concurrent;
21
22 namespace MULTIFORM_PCS.ControlModules.RFID
23 {
24     public class receive
25     {
26         public string[] availablearray=new string[1];
27         public void connect()
28         {
29             try
30             {
31                 Console.WriteLine("Connecting");
32                 TcpClient tcpClient = new TcpClient("192.168.0.100", 8883);
33                 if (tcpClient.Connected)
34                 {
35                     Console.WriteLine("Connected to server");
36                 }
37             }
38             catch (Exception e)
39             {
40                 Console.WriteLine("Connection Failed");
41             }
42         }
43
44         public void reading(CancellationToken ct)
45         {
46             if (ct.IsCancellationRequested == true)
47             {
48                 ct.ThrowIfCancellationRequested();
```

```
49 }
50
51     Console.WriteLine("Connecting");
52     TcpClient tcpClient = new TcpClient("192.168.0.100", 8883);
53
54     if (tcpClient.Connected)
55     {
56         Console.WriteLine("Connected to server");
57     }
58
59     using (StreamReader STR = new StreamReader(tcpClient.GetStream()))
60     {
61         string recieve;
62         char[] trash = new char[16];
63         char[] UID = new char[3];
64         char[] RSSI = new char[3];
65         long milliseconds, seconds, minutes;
66         string UID_, RSSI_, RSSI___;
67         string[] array = new string[1];
68
69         List<string> RSSI__;
70         int UID_DEC=0;
71         int RSSI_int = 0;
72
73         while ((recieve = STR.ReadLine()) != null && !ct.
74                 IsCancellationRequested)
75         {
76             if (ct.IsCancellationRequested)
77             {
78                 try
79                 {
80                     ct.ThrowIfCancellationRequested();
81                 }
82                 catch (AggregateException e)
83                 {
84                 }
85             }
86
87             if (recieve.Contains("+"))
88             {
89
90                 List<string> Worte = recieve.Split(new string[] { "OK",
91                     "<\\r>", "\\n", "", "SCAN:+UID=", "+RSSI=" },
92                     StringSplitOptions.RemoveEmptyEntries).ToList();
93                 string Wort = string.Join("", Worte.ToArray());
94
95                 using (StringReader sr = new StringReader(Wort))
96                 {
97                     sr.Read(trash, 0, 13);
98                     sr.Read(UID, 0, 3);
99                     UID_ = new string(UID);
```

```
97             sr.Read(trash, 0, 1);
98             sr.Read(RSSI, 0, 1);
99             RSSI_ = new string(RSSI);
100            try
101            {
102                UID_DEC = Int32.Parse(UID_, System.Globalization.
103                               NumberStyles.HexNumber);
104            }
105            catch (Exception e)
106            {
107            }
108        }
109
110        RSSI__ = RSSI_.Split(new string[] { "," },
111                               StringSplitOptions.RemoveEmptyEntries).ToList();
112        RSSI___ = string.Join("", RSSI__.ToArray());
113        try
114        {
115            RSSI_int = Int32.Parse(RSSI___);
116        }
117        catch (Exception e)
118        {
119
120            milliseconds = DateTimeOffset.Now.Millisecond;
121            seconds = DateTimeOffset.Now.Second;
122            minutes = DateTimeOffset.Now.Minute;
123            array[0] = minutes + " " + seconds + " " + milliseconds
124            + " " + UID_DEC + " " + RSSI_int;
125            //File.AppendAllText(AppDomain.CurrentDomain.
126            //BaseDirectory + "\\pythonfiles\\python_1robot\\"
127            //RFID_Data.log", minutes + " " + seconds + " "
128            + milliseconds + "\t UID: " + UID_ + " RSSI: " +
129            RSSI___ + "\r");
130            //File.AppendAllText(AppDomain.CurrentDomain.
131            //BaseDirectory + "\\pythonfiles\\python_1robot\\"
132            //RFID_Data_original.log", hour + ":" + minutes + ":" +
133            + seconds + ":" + milliseconds + "\t" + recieve + "\r");
134            //Console.WriteLine(minutes + " " + seconds + " "
135            + milliseconds + "\t" + " " + UID_ + " " + RSSI___);
136        }
137        this.availablearray[0] = array[0];
138    }
139}
140
141
142
143
144    public void disconnect()
145    {
```

```
136     TcpClient tcpClient = new TcpClient();
137     tcpClient.Connect("192.168.0.100", 8883);
138     tcpClient.Close();
139
140 }
141 }
142 }
```

11.3 Appendix C: Initialization procedure (C#)

```

1  using System;
2  using System.Collections.Generic;
3  using System.Linq;
4  using System.Text;
5  using MULTIFORM_PCS.ControlModules.CameraModule.CameraForm;
6  using System.Threading;
7  using MULTIFORM_PCS.GUI;
8  using MULTIFORM_PCS.Gateway.ConnectionModule;
9  using MULTIFORM_PCS.ControlModules.RFID;
10 using System.Threading.Tasks;
11 using System.Collections;
12
13 namespace MULTIFORM_PCS.ControlModules.MPCModule
14 {
15     public class Position
16     {
17         public int X = 0;
18         public int Y = 0;
19     }
20
21     public class PositionD
22     {
23         public double X = 0;
24         public double Y = 0;
25     }
26
27     class Init
28     {
29         //See Appendix D - I
30     }
31 }
```

11.4 Appendix D: Initialization turn and recording Data(C#)

```

1
2     public static void initialize(Int32 time)
3     {
4         int messungen = 100;
5         //Gateway.ConnectionModule.ConnectionCTRLModule.getInstance().
6         //    setCTRLForRobot(0, 0.0, 100.0, 0.0, 8.0, 0.0, 0.0, 3.0);
7         receive initial = new receive();      //Create a new instance of
8         class Receive
9         var tokenSource = new CancellationTokenSource();
10        var token = tokenSource.Token;
11        Init compare = new Init();
12        string[] rfid_signals = new string[messungen];
13        int currentRobot = 0;
14        int[] RobotAssingment = new int[] { 0, 1, 3 };
15        Gateway CTRLModule.getInstance().camCtrl.
16            processFrameAndUpdateGUI();
```

```

14         RobotDescription [] RobotArray = new RobotDescription [] { Gateway
15             .CTRLModule.getInstance().camCtrl.RobotA, Gateway.CTRLModule
16             .getInstance().camCtrl.RobotB,
17             Gateway.CTRLModule.getInstance().camCtrl.RobotC };
18         double [][] velocity1 = new double [RobotArray.Length] [];
19         string[,] Signals = new string[messungen,8];
20         velocity1[currentRobot] = new double[] { 0, 0 }; //Starts the
21             Robot
22         Gateway.CTRLModule.getInstance().getRobotRemoteCTRL(
23             RobotAssingment[currentRobot]).forward(velocity1[
24                 currentRobot], 0, 0, 0); //Sends velocity to Robot
25         //Opening a new Task which works in the background to read data
26             from RFID Antenna
27         Task t = Task.Factory.StartNew(() => initial.reading(token));
28         Thread.Sleep(1000);
29         for (int i = 0; i < 8; i++) //9 Because of 8 measurements
30             every 45 degree
31         {
32             for (int j = 0; j < messungen; j++) //in this for loop we
33                 find all the reachable TAGs
34             {
35                 Signals[j, i] = initial.availablearray[0];
36                 Thread.Sleep(100);
37             }
38             velocity1[currentRobot] = new double[] { 100, -100 }; //
39                 Starts the Robot
40             Gateway.CTRLModule.getInstance().getRobotRemoteCTRL(
41                 RobotAssingment[currentRobot]).forward(velocity1[
42                     currentRobot], 0, 0, 0); //Sends velocity to Robot
43             Thread.Sleep(time); //time the robot needs for a 45 degree
44                 turn
45             velocity1[currentRobot] = new double[] { 0, 0 }; //Stops
46                 the Robot
47             Gateway.CTRLModule.getInstance().getRobotRemoteCTRL(
48                 RobotAssingment[currentRobot]).forward(velocity1[
49                     currentRobot], 0, 0, 0); //Sends velocity to Robot
50         }
51
52         tokenSource.Cancel(); //close the reading Thread
53         try
54         {
55             Task.WaitAll(t);
56         }
57         catch (AggregateException e)
58         {
59         }
60         finally
61         {
62             tokenSource.Dispose();
63         }
64         Console.WriteLine("END\r\n");

```

```

50
51     Array[] Liste = new Array[8]; //List of arrays each array in the
      array contains the data of a special position (45°, 90°,...)
52     string[,] Init_array = new string[8, 14]; //Array filled with
      signal strengthes and ID of every degree position
53     string temp_ID="begin", temp_RSSI; //Substrings of Data
54     int counter; //Counter for the row in the Init_Array
55     Console.WriteLine("");

```

11.5 Appendix E: Filling Array(C#)

```

1  for (int j = 0; j < 8; j++)//converting UID to the specific decimal numbers in
   lookup table
2  {
3      counter = 0;
4      for (int i = 0; i < messungen; i++)
5      {
6          try
7          {
8              temp_ID = Signals[i, j].Substring(Signals[i, j].Length -
6, 4); //seperation of UID in the string
9              if (temp_ID == "2788")
10             {
11                 temp_ID = "1";
12             }
13             if (temp_ID == "1414")
14             {
15                 temp_ID = "2";
16             }
17             if (temp_ID == "3060")
18             {
19                 temp_ID = "3";
20             }
21             if (temp_ID == "1673")
22             {
23                 temp_ID = "4";
24             }
25             if (temp_ID == "1925" || temp_ID == "1025")
26             {
27                 temp_ID = "5";
28             }
29             if (temp_ID == "1681")
30             {
31                 temp_ID = "6";
32             }
33             if (temp_ID == "1146")
34             {
35                 temp_ID = "7";
36             }
37             if (temp_ID == "2780")
38             {
39                 temp_ID = "8";

```

```

40
41         }
42         if (temp_ID == "1933")
43         {
44             temp_ID = "9";
45         }
46     catch (AggregateException e)
47     {
48         Console.WriteLine("Array incomplete");
49     }
50
51     temp_RSSI = Signals[i, j].Substring(Signals[i, j].Length -
52                                         1, 1); //seperation of RSSI in the string
53     if (temp_ID != Init_array[j, 0] && temp_ID != Init_array[j,
54                                         1] && temp_ID != Init_array[j, 2] && temp_ID !=
55                                         Init_array[j, 3] && temp_ID != Init_array[j, 4] &&
56                                         temp_ID != Init_array[j, 5] && temp_ID != Init_array[j,
57                                         6] && temp_ID != Init_array[j, 7]) //check if the UID
58                                         already exists in the Init_array
59     {
59         //Filling Init_Array
60         Init_array[j, counter] = temp_ID;
61         Init_array[j, counter + 7] = temp_RSSI;
62         counter++;
63     }
64 }
65 }
```

11.6 Appendix F: Checking for solutions in array(C#)

```

1 int rowLength = Init_array.GetLength(0);
2         int colLength = Init_array.GetLength(1);
3         string str;
4         string headline = "| " + "ID 1" + " | " + "ID 2" + " | " + "ID 3" + "
5             | " + "ID 4" + " | " + "ID 5" + " | " + "ID 6" + " | " + "ID 7" +
6             " | " + "ST 1" + " | " + "ST 2" + " | " + "ST 3" + " | " + "ST 4" +
7             " | " + "ST 5" + " | " + "ST 6" + " | " + "ST 7" + " | ";
8         System.Console.WriteLine(headline);
9
10        for (int k = 0; k < rowLength; k++)
11        {
12            str = "| " + Init_array[k, 0] + " | " + Init_array[k, 1] + "
13                | " + Init_array[k, 2] + " | " + Init_array[k, 3] + "
14                | " + Init_array[k, 4] + " | " + Init_array[k, 5] + "
15                | " + Init_array[k, 6] + " | " + Init_array[k, 7] + "
16                | " + Init_array[k, 8] + " | " + Init_array[k, 9] + "
17                | " + Init_array[k, 10] + " | " + Init_array[k, 11] +
18                " | " + Init_array[k, 12] + " | " + Init_array[k, 13]
19                + " | ";
20            System.Console.WriteLine(str);
21        }
22 }
```

```
13 // Solver
14 // Different Positions
15 Position Starting = new Position();
16 Position Antenna1 = new Position();
17 Position Antenna2 = new Position();
18 Position Antenna3 = new Position();
19 Position Antenna4 = new Position();
20
21 //Initialization for Position estimation
22 float m1 = 0.000f;
23 float m2 = 0.000f;
24
25 float RobStartx_fl = 0.000f;
26 float RobStarty_fl = 0.000f;
27
28 double angle;
29 double angleTemp;
30
31 int null_counter = 0;
32 int[] check_row = new int[8];
33 for (int m = 0; m < rowLength; m++)
34 {
35     null_counter = 0;
36     for (int n = 0; n < 7; n++)
37     {
38         if (Init_array[m, n] == null)
39         {
40             null_counter++;
41         }
42     }
43     check_row[m] = 7 - null_counter; //Array of elements with
        the number empty places of each init_array row
44 System.Console.WriteLine("The number of elements at " + m *
        45 + "° is: \t" + check_row[m]);
45 }
46 bool solution_found = false; //true if initialization process
        is solvable
47 bool solution1_found = false; //true if one possible point is
        found
48 bool solution2_found = false; //true if two possible points
        are found
49 int count = 0;
50 int[] solution1 = new int[2]; //Array with the both degree
        numbers of solution 1
51 int[] solution2 = new int[2]; //Array with the both degree
        numbers of solution 2
52 while (solution_found == false)
53 {
54     while (solution1_found == false)
55     {
56         if (check_row[count] >= 3)
```

```
57         {
58             if (check_row[count + 4] >= 3)
59             {
60                 solution1[0] = count;
61                 solution1[1] = count + 4;
62                 break;
63             }
64             if (count >= 2)      //if we reach the 180 degree
65             there will be no solution for this
66             initialization turn
67             {
68                 System.Console.WriteLine("NO SOLUTION FOUND!!!")
69                 ;
70                 break;
71             }
72             count++;
73         }
74         System.Console.WriteLine(count);
75         count = count + 1;
76         while (solution2_found == false)
77         {
78             if (check_row[count] >= 3)
79             {
80                 if (count >= 8)
81                 {
82                     Console.WriteLine("Out of Range Exception caused
83                     in Array: " + count);
84                 }
85                 if (check_row[count + 4] >= 3)
86                 {
87                     solution2[0] = count;
88                     solution2[1] = count + 4;
89                     solution_found = true;
90                     break;
91                 }
92                 if (count >= 3)      //if we reach the 180 degree
93                 there will be no solution for this
94                 initialization turn
95                 {
96                     System.Console.WriteLine("NO SOLUTION FOUND!!!")
97                     ;
98                     break;
99                 }
100 }
```

```

101         System.Console.WriteLine("Solution No. 1 found at: " +
102             solution1[0] * 45 + " degree -- " + solution1[1] * 45 +
103             " degree");
104         System.Console.WriteLine("Solution No. 2 found at: " +
105             solution2[0] * 45 + " degree -- " + solution2[1] * 45 +
106             " degree");
107     }

```

11.7 Appendix G: Position and orientation estimation(C#)

```

1 // Providing the distance with the highest probability
2 // Input: # of tags, all IDs of the tags
3 // Output: best fitting IDs (e.g. [3 4 5] if 3rd, 4th and 5th
4 //          are best ones)
5 //          the correct distance <-> RSSI signal (e.g. [2 1 3]
6 //          for middle, max and min)
7 int[,] best_arr1 = new int[2, 3];
8 int[,] best_arr2 = new int[2, 3];
9 int[,] best_arr3 = new int[2, 3];
10 int[,] best_arr4 = new int[2, 3];
11
12 int[] temp_input1 = new int[7];
13 int[] temp_input2 = new int[7];
14 int[] temp_input3 = new int[7];
15 int[] temp_input4 = new int[7];
16
17 int[] temp_inputRSSI1 = new int[7];
18 int[] temp_inputRSSI2 = new int[7];
19 int[] temp_inputRSSI3 = new int[7];
20 int[] temp_inputRSSI4 = new int[7];
21
22 for (int i = 0; i < 8; i++)
23 {
24     for (int j = 0; j < 14; j++)
25     {
26         if (Init_array[i, j] == null)
27         {
28             Init_array[i, j] = "0";
29         }
30     }
31
32     for (int m = 0; m < 7; m++)
33     {
34         temp_input1[m] = Int32.Parse(Init_array[solution1[0], m]);
35         temp_input2[m] = Int32.Parse(Init_array[solution1[1], m]);
36         temp_input3[m] = Int32.Parse(Init_array[solution2[0], m]);
37         temp_input4[m] = Int32.Parse(Init_array[solution2[1], m]);
38
39         temp_inputRSSI1[m] = Int32.Parse(Init_array[solution1[0], m
40             + 7]);

```



```

62
63
64
65
66
67
68
69
70
71
72
73
74
75
76
77
78
79
80
81
82
83
84
85
86
    (Init_array[solution2[0], best_arr3
    [0, 0] + 7]),
    Int32.Parse(Init_array[solution2[0],
    best_arr3[0, 1] + 7]), Int32.Parse(
    Init_array[solution2[0], best_arr3
    [0, 2] + 7]),
    best_arr3[1, 0], best_arr3[1, 1],
    best_arr3[1, 2]);
64
65
Antenna4 = Trilateration(IDtoPOS(Int32.Parse(Init_array[
    solution2[1], best_arr4[0, 0]])), IDtoPOS(Int32.Parse(
    Init_array[solution2[1], best_arr4[0, 1]])),
IDtoPOS(Int32.Parse(Init_array[solution2
    [1], best_arr4[0, 2]])), Int32.Parse(
    Init_array[solution2[1], best_arr4
    [0, 0] + 7]),
Int32.Parse(Init_array[solution2[1],
    best_arr4[0, 1] + 7]), Int32.Parse(
    Init_array[solution2[1], best_arr4
    [0, 2] + 7]),
best_arr4[1, 0], best_arr4[1, 1],
best_arr4[1, 2]);
66
67
68
69
70
    Console.WriteLine("1st Antenna " + Antenna1.X + " and " +
        Antenna1.Y);
    Console.WriteLine("2nd Antenna " + Antenna2.X + " and " +
        Antenna2.Y);
    Console.WriteLine("3rd Antenna " + Antenna3.X + " and " +
        Antenna3.Y);
    Console.WriteLine("4th Antenna " + Antenna4.X + " and " +
        Antenna4.Y);
71
72
73
74
    //Console.ReadKey();
    // Alternative estimation of the centre of the robot + position
    //m1 = ((float)Antenna2.Y - (float)Antenna1.Y) / ((float)
    //    Antenna2.X - (float)Antenna1.X);
    //m2 = ((float)Antenna4.Y - (float)Antenna3.Y) / ((float)
    //    Antenna4.X - (float)Antenna3.X);
    //RobStartx_fl = (1 / (m1 - m2)) * (m1 * (float)Antenna1.X - m2
    //    * (float)Antenna3.X - (float)Antenna1.Y + (float)Antenna3.Y)
    ;
    //RobStarty_fl = m1 * (RobStartx_fl - (float)Antenna1.X) + (
    //    float)Antenna1.Y;
75
76
77
78
79
79
80
81
82
83
84
85
Starting.X = (((Antenna4.X-Antenna3.X)*(Antenna2.X*Antenna1.Y-
    Antenna1.X*Antenna2.Y)-(Antenna2.X-Antenna1.X)*(Antenna4.X*
    Antenna3.Y-Antenna3.X*Antenna4.Y)) /
    ((Antenna4.Y - Antenna3.Y) * (Antenna2.X -

```

```

87                                         Antenna1.X) - (Antenna2.Y - Antenna1.Y)
88                                         * (Antenna4.X - Antenna3.X)));
Starting.Y = (((Antenna1.Y - Antenna2.Y) * (Antenna4.X *
89                                         Antenna3.Y - Antenna3.X * Antenna4.Y) - (Antenna3.Y -
90                                         Antenna4.Y) * (Antenna2.X * Antenna1.Y - Antenna1.X *
91                                         Antenna2.Y)) /
92                                         ((Antenna4.Y - Antenna3.Y) * (Antenna2.X -
93                                         Antenna1.X) - (Antenna2.Y - Antenna1.Y)
94                                         * (Antenna4.X - Antenna3.X));
95
96                                         Console.WriteLine("Robotstarting Position at:" + Starting.X +
97                                         "mm, " + Starting.Y + "mm");
98
99                                         // Computing the orientation of the Robot
100                                        //angle = (Math.Atan2(y, x)) * (180 / Math.PI);
101                                        angleTemp = (Math.Atan2((Antenna1.Y - Starting.Y), (Antenna1.X -
102                                         Starting.X)) * (180 / Math.PI));
103
104                                         Console.WriteLine("Angle temp " + angleTemp);
105                                         angle = angleTemp - (double)(solution1[0]*45.0); // in deg
106                                         Console.WriteLine("Angle wrong direction " + angle);
107                                         if (angle <= 0.0)
108                                         {
109                                             angle = angle + 180;
110                                         }
111                                         else
112                                         {
113                                             angle = angle - 180;
114                                         }
115
116                                         Console.WriteLine("Robotangle: " + angle + "Â°");
117
118                                         }

```

11.8 Appendix H: Initialization procedure 3(C#)

```

1 // Procedure and function
2 //Methode to compute the position based on the ID in [cm], Output in [mm]
3     public static Position Trilateration(Position point1, Position point2,
4                                         Position point3, int r1t, int r2t, int r3t, int bestr1, int bestr2,
5                                         int bestr3)
6     {
7         //double[] dist = new double[] { 10.5, 10.0, 9.5, 9.0, 8.0, 6.0,
8             5.0, 4.0 }; // FH paper
9         double[,] dist = new double[3, 8] { { 14, 9.75, 9.0, 8.0, 7.0, 6.0,
10             3.5, 2.75 },
11                 { 5.0, 5.1, 5.3, 5.5, 5.8, 4.0,
12                   3.5, 2.75 },
13                 { 5.0, 4.7, 4.5, 4.3, 4.2, 4.0,
14                   3.5, 2.75 } }; //
15             Approximation of our
16             measurements
17
18 }
```

```
10          Position resultPose = new Position();
11          PositionD ex = new PositionD();
12          PositionD ey = new PositionD();
13          PositionD aux = new PositionD();
14          PositionD auy = new PositionD();
15          PositionD aux2 = new PositionD();
16          double r1;
17          double r2;
18          double r3;
19          r1 = dist[bestr1, r1t];
20          r2 = dist[bestr2, r2t];
21          r3 = dist[bestr3, r3t];
22
23          // For testing purpose
24          //Console.WriteLine("1st radius " + r1);
25          //Console.WriteLine("2nd radius " + r2);
26          //Console.WriteLine("3rd radius " + r3);
27
28          //Console.WriteLine("1st point " + point1.X + " " + point1.Y);
29          //Console.WriteLine("2nd point " + point2.X + " " + point2.Y);
30          //Console.WriteLine("3rd point " + point3.X + " " + point3.Y);
31
32          //unit vector in a direction from point1 to point 2
33          double p2p1Distance = Math.Pow(Math.Pow(point2.X - point1.X, 2) +
34                                         Math.Pow(point2.Y - point1.Y, 2), 0.5);
35          ex.X = (point2.X - point1.X) / p2p1Distance;
36          ex.Y = (point2.Y - point1.Y) / p2p1Distance;
37          aux.X = point3.X - point1.X;
38          aux.Y = point3.Y - point1.Y;
39          //signed magnitude of the x component
40          double i = ex.X * aux.X + ex.Y * aux.Y;
41          //the unit vector in the y direction.
42          aux2.X = point3.X - point1.X - i * ex.X;
43          aux2.Y = point3.Y - point1.Y - i * ex.Y;
44          ey.X = aux2.X / Norm(aux2);
45          ey.Y = aux2.Y / Norm(aux2);
46          //the signed magnitude of the y component
47          double j = ey.X * aux.X + ey.Y * aux.Y;
48          //coordinates
49          double x = (Math.Pow(r1, 2) - Math.Pow(r2, 2) + Math.Pow(
50                         p2p1Distance, 2)) / (2 * p2p1Distance);
51          double y = (Math.Pow(r1, 2) - Math.Pow(r3, 2) + Math.Pow(i, 2) +
52                         Math.Pow(j, 2)) / (2 * j) - i * (x / j);
53
54          //result coordinates
55          double finalX = 10 * (point1.X + x * ex.X + y * ey.X);
56          double finalY = 10 * (point1.Y + x * ex.Y + y * ey.Y);
57          resultPose.X = (int)(finalX);
58          resultPose.Y = (int)(finalY);
59
60          return resultPose;
61      }
```

11.9 Appendix I: Initialization procedure 4(C#)

```

1      // Method to compute the norm of a vector
2      public static double Norm(PositionD p) // get the norm of a vector
3      {
4          return (Math.Pow(Math.Pow(p.X, 2) + Math.Pow(p.Y, 2), 0.5));
5      }
6
7      // Methode to compute the position based on the ID in [mm]
8      public static Position IDtoPOS(int ID)
9      {
10         Position FinalPos = new Position();
11         int[] posx = new int[9] { 10, 10, 10, 20, 20, 20, 30, 30, 30 };
12         int[] posy = new int[9] { 10, 20, 30, 10, 20, 30, 10, 20, 30 };
13         // For a 3x3 testing field
14         FinalPos.X = posx[ID - 1];
15         FinalPos.Y = posy[ID - 1];
16         return FinalPos;
17     }
18 }
```

11.10 Appendix J: Initialization procedure 5(C#)

```

1 // Find neighbours of the IDs
2     public static int[] FindNeig(int[] arrID, int numTags)
3     {
4         // Init
5         int[] neighbours = new int[numTags];
6         int[] tempNeig = new int[4];
7
8         // Find the number of neighbours
9         for (int m = 0; m < numTags; m++)
10        {
11            // Init
12            neighbours[m] = 0;
13
14            // Take actual ID and compute the possible neighbours
15            tempNeig[0] = arrID[m] - 11;
16            tempNeig[1] = arrID[m] - 1;
17            tempNeig[2] = arrID[m] + 1;
18            tempNeig[3] = arrID[m] + 11;
19
20            for (int v = 0; v < 4; v++)
21            {
22                foreach (int tempinput in arrID)
23                {
24                    if (tempinput == tempNeig[v])
25                    {
26                        neighbours[m] += 1;
27                    }
28                }
29            }
40        }
41    }
42 }
```

```

30         }
31     return neighbours;
32 }
```

11.11 Appendix K: Initialization procedure 6(C#)

```

1 // Methode to compute the best IDs and correct distances
2     public static int[,] CorrectID_Distance(int[] arr, int[] arrRSSI, int
3         numTags)
4     {
5         // Inputs
6         /* arr = Array of all IDs
7          * arrRSSI = Array of all RSSI
8          numTags = Int with the num of tags found
9         */
10        // Init
11        int[,] best = new int[2, 3];
12        int[] dist = new int[numTags];           // Array which contain the
13            best distance (max(0), middle(1), min(2))
14        int[] neighbours = new int[numTags];
15        int i = 0;
16        int p = 4;
17
18
19
20        // Compute the neighbours
21        neighbours = FindNeig(arr, numTags);
22
23
24        // Switch case for the different possible shapes
25        switch (numTags)
26        {
27            case 3:
28                Console.WriteLine("3 Tags -----");
29                for (int l = 0; l < neighbours.GetLength(0); l++)
30                {
31                    if (neighbours[l] == 0)      // Detect outlier and
32                        boarder
33                    {
34                        dist[l] = 1;           // stay max
35                    }
36                    else if (neighbours[l] <= 3)    // Detect outlier and
37                        boarder
38                    {
39                        dist[l] = 0;           // stay max
40                    }
41                    else if (neighbours[l] == 4)    // Detect the inner,
42                        change it to min/middle
43                    {
44                        dist[l] = 1;           // change it to middle
45                    }
46                    else if (neighbours[l] > 4)    // Detect the inner,
47                        change it to min/middle
48                    {
49
```

```

41             dist[l] = 0;           // change it to middle
42         }
43         // all other numbers are at the boarder
44     }
45     // Select the best 3 readings
46     i = 0;
47     p = 4;
48     while (i < 3)           // Start for the first ID
49     {
50         for (int h = 0; h < neighbours.GetLength(0); h++) // looks for a fitting
51         {
52             if (neighbours[h] == p && i < 3) // hit must be same value and less then 3 hits
53             {
54                 best[0, i] = h;           // index of the best ID
55                 best[1, i] = dist[h];   // info about max, mid and min of this ID
56                 i += 1;
57             }
58             else if (i >= 3)
59             {
60                 break;
61             }
62         }
63         p -= 1;
64     }
65     break;
66 /*
-----*/
67 case 4:
68     Console.WriteLine("4 Tags -----");
69     for (int l = 0; l < neighbours.GetLength(0); l++)
70     {
71         if (neighbours[l] == 0)           // Detect outlier and boarder
72         {
73             dist[l] = 1;               // stay max
74         }
75         else if (neighbours[l] <= 3)    // Detect outlier and boarder
76         {
77             dist[l] = 0;               // stay max
78         }
79         else if (neighbours[l] == 4)    // Detect the inner, change it to min/middle
80         {
81             dist[l] = 1;               // change it to middle
82         }

```

```
83         else if (neighbours[l] > 4)      // Detect the inner,
84             change it to min/middle
85         {
86             dist[l] = 0;                  // change it to middle
87         }
88         // all other numbers are at the boarder
89     }
90     // Select the best 3 readings
91     i = 0;
92     p = 4;
93     while (i < 3)                      // Start for the first ID
94     {
95         for (int h = 0; h < neighbours.GetLength(0); h++) // looks for a fitting
96         {
97             if (neighbours[h] == p && i < 3) // hit must be
98                 same value and less then 3 hits
99             {
100                 best[0, i] = h;           // index of the
101                 best ID
102                 best[1, i] = dist[h]; // info about
103                     max, mid and min of this ID
104                 i += 1;
105             }
106         }
107         else if (i >= 3)
108         {
109             break;
110         }
111     }
112     p -= 1;
113     break;
114 /*
-----*/
115 case 5:
116     Console.WriteLine("5 Tags -----");
117     for (int l = 0; l < neighbours.GetLength(0); l++)
118     {
119         if (neighbours[l] <= 2)      // Detect outlier and
120             boarder
121         {
122             dist[l] = 0;              // stay max
123         }
124         else if (neighbours[l] == 3) // Detect the inner,
125             change it to min/middle
126         {
127             dist[l] = 1;              // change it to middle
128         }
129         // all other numbers are at the boarder
```

```

125
126 }  

127 // Select the best 3 readings  

128 i = 0;  

129 p = 4;  

130 while (i < 3) // Start for the first ID  

131 {  

132     for (int h = 0; h < neighbours.GetLength(0); h++) //  

133         looks for a fitting  

134     {  

135         if (neighbours[h] == p && i < 3) // hit must be  

136             same value and less than 3 hits  

137         {  

138             best[0, i] = h; // index of the  

139             best ID  

140             best[1, i] = dist[h]; // info about  

141                 max, mid and min of this ID  

142             i += 1;  

143         }  

144         else if (i >= 3)  

145         {  

146             break;  

147         }  

148     }  

149     p -= 1;  

150 }  

151 break;  

152 /*-----*/  

153 */  

154 case 6:  

155     Console.WriteLine("6 Tags -----");  

156     switch (neighbours.Sum())  

157     {  

158         case 12: // Shape with 2 outliers  

159         Console.WriteLine("2 Outliers");  

160         for (int l = 0; l < neighbours.GetLength(0); l++)  

161         {  

162             if (neighbours[l] <= 2) // Detect outlier  

163                 and border  

164             {  

165                 dist[l] = 0; // stay max  

166             }  

167             else if (neighbours[l] == 4) // Detect the  

168                 inner, change it to min/middle  

169             {  

170                 if (arrRSSI[l] <= 3)  

171                 {  

172                     dist[l] = 2; // change it to  

173                         min  

174                 }  

175             }  

176         }  

177     }

```

```

167     else if (arrRSSI[1] > 3)
168     {
169         dist[1] = 1;                                // change it to
170         middle
171     }
172     // all other numbers are at the boarder
173 }
174 break;
175 case 14: // Shape like a domino
176     Console.WriteLine("Domino");
177     for (int l = 0; l < neighbours.GetLength(0); l++)
178     {
179         if (neighbours[l] <= 2)           // Detect outlier
180             and boarder
181         {
182             dist[l] = 0;                  // stay max
183         }
184         else if (neighbours[l] == 3)      // Detect the
185             centre, change it to min
186         {
187             dist[l] = 2;                  // change it to min
188         }
189         // all other numbers are at the boarder
190     }
191     break;
192 default:
193     Console.WriteLine("Default case");
194     break;
195 }
196 // Select the best 3 readings
197 i = 0;
198 p = 4;
199 while (i < 3)                                // Start for the first ID
200 {
201     for (int h = 0; h < neighbours.GetLength(0); h++) // looks for a fitting
202     {
203         if (neighbours[h] == p && i < 3) // hit must be
204             same value and less than 3 hits
205         {
206             best[0, i] = h;                // index of the
207             best ID
208             best[1, i] = dist[h];        // info about
209             max, mid and min of this ID
210             i += 1;
211         }
212         else if (i >= 3)
213         {
214             break;
215         }

```

```
211         }
212         p -= 1;
213     }
214
215     break;
216 /*
-----*/
217 case 7:
218     Console.WriteLine("7 Tags -----");
219     for (int l = 0; l < neighbours.GetLength(0); l++)
220     {
221         if (neighbours[l] <= 3)           // Detect outlier and
222             boarder
223         {
224             dist[l] = 0;                  // stay max
225         }
226         else if (neighbours[l] == 4)      // Detect the centre,
227             change it to min
228         {
229             dist[l] = 2;                  // change it to min
230         }
231         // all other numbers are at the boarder
232     }
233     // Select the best 3 readings
234     i = 0;
235     p = 4;
236     while (i < 3)                      // Start for the first ID
237     {
238         for (int h = 0; h < neighbours.GetLength(0); h++) // looks for a fitting
239         {
240             if (neighbours[h] == p && i < 3) // hit must be
241                 same value and less then 3 hits
242             {
243                 best[0, i] = h;            // index of the
244                 best ID
245                 best[1, i] = dist[h];    // info about
246                 max, mid and min of this ID
247                 i += 1;
248             }
249             else if (i >= 3)
250             {
251                 break;
252             }
253         }
254         p -= 1;
255     }
256     break;
257 default:
258     Console.WriteLine("Default case");
```

```

254         break;
255     }
256     foreach (int ee in best)
257     {
258         Console.WriteLine(ee);
259     }
260     return best;
261 }

```

11.12 Appendix L: Initialization procedure 7(C#)

```

1  //Method to compute the position based on the ID in [cm], Output in [mm]
2  public static Position Trilateration(Position point1, Position point2,
3      Position point3, int r1t, int r2t, int r3t, int bestr1, int bestr2,
4      int bestr3)
5  {
6      //double[] dist = new double[] { 10.5, 10.0, 9.5, 9.0, 8.0, 6.0,
7      //    5.0, 4.0 }; // FH paper
8      double[,] dist = new double[3, 8] { { 14, 9.75, 9.0, 8.0, 7.0, 6.0,
9          3.5, 2.75 },
10         { 5.0, 5.1, 5.3, 5.5, 5.8, 4.0,
11             3.5, 2.75 },
12         { 5.0, 4.7, 4.5, 4.3, 4.2, 4.0,
13             3.5, 2.75 } }; // Approximation of our
14         measurements
15
16         Position resultPose = new Position();
17         PositionD ex = new PositionD();
18         PositionD ey = new PositionD();
19         PositionD aux = new PositionD();
20         PositionD auy = new PositionD();
21         PositionD aux2 = new PositionD();
22         double r1;
23         double r2;
24         double r3;
25         r1 = dist[bestr1, r1t];
26         r2 = dist[bestr2, r2t];
27         r3 = dist[bestr3, r3t];
28
29         // For testing purpose
30         //Console.WriteLine("1st radius " + r1);
31         //Console.WriteLine("2nd radius " + r2);
32         //Console.WriteLine("3rd radius " + r3);
33
34         //Console.WriteLine("1st point " + point1.X + " " + point1.Y);
35         //Console.WriteLine("2nd point " + point2.X + " " + point2.Y);
36         //Console.WriteLine("3rd point " + point3.X + " " + point3.Y);
37
38         //unit vector in a direction from point1 to point 2
39         double p2p1Distance = Math.Pow(Math.Pow(point2.X - point1.X, 2) +
40             Math.Pow(point2.Y - point1.Y, 2), 0.5);

```

```
33     ex.X = (point2.X - point1.X) / p2p1Distance;
34     ex.Y = (point2.Y - point1.Y) / p2p1Distance;
35     aux.X = point3.X - point1.X;
36     aux.Y = point3.Y - point1.Y;
37     //signed magnitude of the x component
38     double i = ex.X * aux.X + ex.Y * aux.Y;
39     //the unit vector in the y direction.
40     aux2.X = point3.X - point1.X - i * ex.X;
41     aux2.Y = point3.Y - point1.Y - i * ex.Y;
42     ey.X = aux2.X / Norm(aux2);
43     ey.Y = aux2.Y / Norm(aux2);
44     //the signed magnitude of the y component
45     double j = ey.X * aux.X + ey.Y * aux.Y;
46     //coordinates
47     double x = (Math.Pow(r1, 2) - Math.Pow(r2, 2) + Math.Pow(
48         p2p1Distance, 2)) / (2 * p2p1Distance);
49     double y = (Math.Pow(r1, 2) - Math.Pow(r3, 2) + Math.Pow(i, 2) +
50         Math.Pow(j, 2)) / (2 * j) - i * (x / j);
51     //result coordinates
52     double finalX = 10 * (point1.X + x * ex.X + y * ey.X);
53     double finalY = 10 * (point1.Y + x * ex.Y + y * ey.Y);
54     resultPose.X = (int)(finalX);
55     resultPose.Y = (int)(finalY);
56
57     return resultPose;
58 }
```

11.13 Appendix M: WeMos D1 Mini (Arduino)

```
1 #include <SoftwareSerial.h>
2 #include <ESP8266WiFi.h>
3 #include <ESP8266HTTPClient.h>
4 #include <string.h>
5 #include <ArduinoJson.h>
6
7
8 //how many clients should be able to telnet to this ESP8266
9 #define MAX_SRV_CLIENTS 2
10
11 // Definig Wifi address, password, host and port
12 //const char* ssid      = "UPC113C854 A.Abouelkhair";      // write SSID between "( here )"
13 //const char* password = "rnU3cu6dzpkA";                      // write Password between
14 //const char* ssid      = "iPhone";                            // write SSID between "( here )"
15 //const char* password = "boody123";                          // write Password between
16 //const char* ssid      = "iRobot";                            // write SSID between "( here )"
17 //const char* password = "nopipes123";                         // write Password between "( case sensitve)"
18 //const char* ssid      = "DORTMUND-DEMO-AP";                  // write SSID
19 //const char* password = "R0b0tn1K";                           // write Password between "( case sensitve)"
20
21 // Starting Wifi Server and client with Port 8883
22 WiFiServer server(8883);
23 WiFiClient serverClients[MAX_SRV_CLIENTS];
24
25 // Variables Declaration
26 unsigned long previousMillis = 0;
27 const long interval = 10;
28 unsigned long currentTime;
29
30 /* RFID Intialization */
31 SoftwareSerial RFID(14, 12, false, 256);      //RX,TX = D5,D6 (Wemos UART1)
32
33
34
35
36 void setup() {
37     // put your setup code here, to run once:
38
39     /* Beginning Serial Communication with RFID with baud rate 115200 */
40     RFID.begin(115200);
41     // delay(10);
```

```
42 // Beginning Serial Communication with baud rate 115200
43 Serial.begin(115200);
44 // delay(10);
45 Serial.println();
46
47
48 Serial.println();
49 Serial.print("Connecting to ");
50 Serial.println(ssid);
51
52 // Time is used so the device does not stuck in
53 // connecting to Wifi forever
54 currentTime = millis();
55 unsigned long previousTime = currentTime;
56 while (WiFi.status() != WL_CONNECTED) {
57     delay(500);
58     Serial.print(".");
59     currentTime = millis();
60     if ((currentTime - previousTime) > 12000) {
61         break;
62     }
63 }
64
65
66 WiFi.mode(WIFI_STA);
67 WiFi.begin(ssid, password);
68 uint8_t i = 0;
69 while (WiFi.status() != WL_CONNECTED && i++ < 20) delay(500);
70 if (i == 21) {
71     Serial.print("Could not connect to"); Serial.println(ssid);
72     while (1) delay(500);
73 }
74 server.begin();
75 server.setNoDelay(true);
76
77
78 // Getting the MAC address and saving it
79 if (WiFi.status() == WL_CONNECTED) {
80     Serial.println("");
81     Serial.println("WiFi connected");
82     Serial.print("IP address: ");
83     Serial.println(WiFi.localIP());
84     Serial.println("Port: 8883");
85 }
86
87 /* AUTO Send AT Command to the RFID */
88 RFID.write("AT+Scan=OFF\r");
89 // RFID.write("AT+Scan=AC,RSSI\r");
90 RFID.write("AT+Scan=AC,RSSI\r");
91
92 // delay(10);
```

```
93
94
95  }
96
97
98 void loop() {
99     // put your main code here, to run repeatedly
100
101    // while(RFID.available())
102    //
103    //     char read= RFID.read();
104    //     Serial.print(read);
105    //     delay(10);
106    //
107
108    /*Send commands Through Wifi*/
109    sendCommandsWiFi();
110
111    /* send AT Commands to RFID through serial monitor */
112    //Example: AT+Scan=AC,RSSI           "Without /r"
113    // Comment the next command if you are using AUTO command send
114    sendCommandsRFID();
115
116
117 }
118
119
120
121 void sendCommandsWiFi()
122 {
123
124     unsigned long currentMillis = millis();
125     uint8_t i;
126     //check if there are any new clients
127     if (server.hasClient()) {
128         for (i = 0; i < MAX_SRV_CLIENTS; i++) {
129             //find free/disconnected spot
130             if (!serverClients[i] || !serverClients[i].connected()) {
131                 if (serverClients[i]) serverClients[i].stop();
132                 serverClients[i] = server.available();
133                 continue;
134             }
135         }
136         //no free/disconnected spot so reject
137         WiFiClient serverClient = server.available();
138         serverClient.stop();
139     }
140
141     //do every 2ms edit from time interval in Declaration
142     // if (currentMillis - previousMillis >= interval)      //
143     // { //
```

```
144 //     previousMillis = currentMillis;  //
145     for (i = 0; i < MAX_SRV_CLIENTS; i++)
146     {
147         if (serverClients[i] && serverClients[i].connected())
148         {
149             delay(20);
150             RFID.write("AT+A\r");
151             while(RFID.available()>0)
152             {
153                 char read = RFID.read();
154                 serverClients[i].print(read);
155             }
156         }
157     }
158 }
159 // } //
160 }
161 }
162
163
164 void sendCommandsRFID()
165 {
166     /* send AT Commands to RFID through serial monitor */
167     //Example: AT+Scan=AC,RSSI           "Without \r"
168     while (Serial.available() > 0) {
169         RFID.write(Serial.read());
170     }
171 }
172 }
```

11.14 Appendix N: Communication Outlay

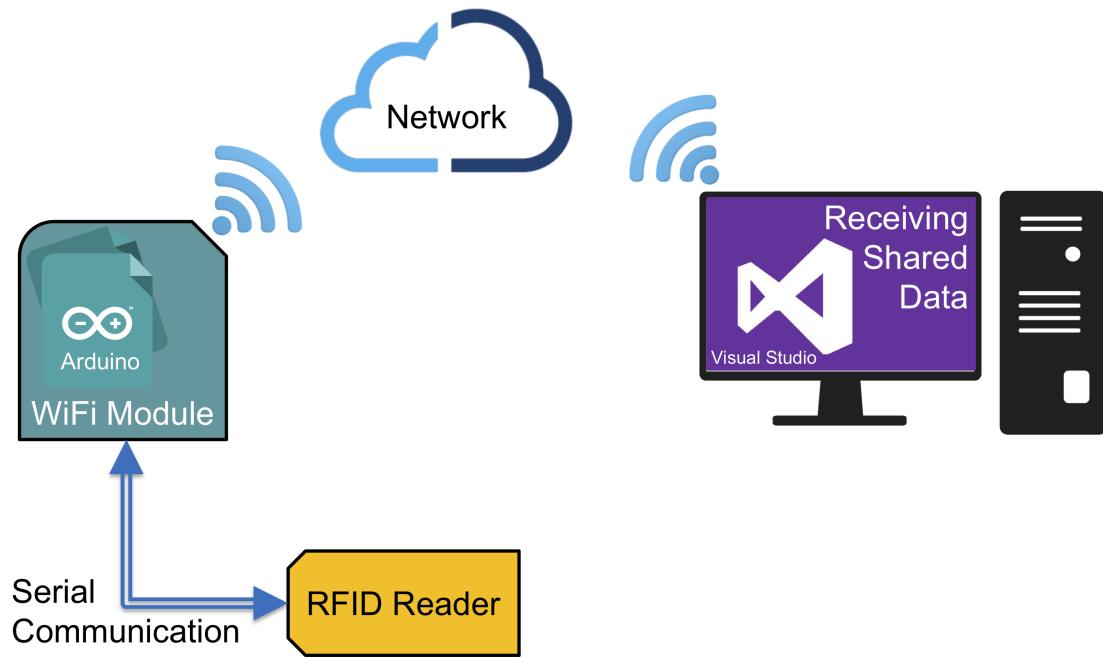


Figure 44: Communication Outlay