ISSN(Online): 2320-9801
ISSN (Print): 2320-9798

International Journal of Innovative Research in Computer and Communication Engineering

(An ISO 3297: 2007 Certified Organization)

Vol. 3, Issue 4, April 2015

Localization of Wireless Sensor Networks with Ranging Quality in Woods

[1]Navinkumar Dhopre, [2]Shital Y Gaikwad

[1]M. E. (Second Year Student), Department of CSE, MPGI Institute of Engineering and Technology, Kupsurwadi, Nanded. (M.S.), India.

[2]Professor, Department of CSE, MPGI Institute of Engineering and Technology, Kupsurwadi, Nanded. (M.S.), India.

ABSTRACT: Localization is becoming very efficient and attractive in wireless sensor networks. Localization is most challenging and newest technology in real-world experience. When we use it in the forest there are various challenging interfering factors are there. Today wireless sensor networks are broadly used in control on environment , surveillance missions, monitoring, tracking and controlling etc. This localization is achieved by WSN and it is based on broadcasting technology exists in open field and it needs unbreakable communication. This paper deals with, *C*ombined and *D*ifferentiated *L*ocalization idea for localization. That helps to exploits the strength of range-free approaches and range-based approaches. All this is possible by using received signal strength indicator (RSSI). As per study it is observed that ranging quality will effect on the accuracy of localization. Then for better ranging quality, CDL method is used. This combines virtual-hop localization, local filtration, ranging-quality aware calibration. It provides more accurate and consistent performance.

KEYWORDS: RSSI,CDL,WSN, AoA

I. INTRODUCTION

Wireless networks of sensors greatly extend our ability to monitor and control the physical world. The availability of micro sensors and low power wireless communications enables the deployment of densely distributed sensor/actuator networks for a wide range of biological and environmental monitoring applications, sea marine to soil, atmospheric contexts. Sensors of particular network can collaborate and aggregate the huge amount of sensed data to provide continuous and spatially dense observation of biological, environmental and artificial systems In these large sensor network systems, we need nodes to be able to locate themselves in various environments, and on different distance scales.[1] In these large sensor network systems, we need nodes to be able to locate themselves in various environments, and on different distance scales. [2] Many localization algorithms for sensor networks have been proposed to provide per-node location information. With regard to the mechanisms used for finding location, we divide these localization protocols into two categories: range-based and range-free. [3] Imagine a network of sensors sprinkled across a large building or an area such as a forest. Typical tasks for such networks are to send a message to a node at a given location (without knowing which node r nodes are there or how to get there), to retrieve sensor data (e.g., sound or temperature levels) from nodes in a given region.[21] Many ideas have been proposed for node localization in WSN. Based on whether accurate ranging is required, there are basically two types of methods: (i) range-based localization and (ii) range-free localization. Range-based localization could achieve good accuracy but costly.[28] Range-based approaches measure the Euclidean distances among the nodes with various ranging techniques [16], [20], [25]. They are either expensive with respect to hardware, or environmental noises and dynamics [23]. Range-free approaches perform localization by relying only on network connectivity measurements. Therefore , localization results by range-free approaches are typically imprecise and easily affected by node density. Range-free localization techniques are more cost-effective and less limited for a wider range of applications in WSNs than range-based techniques. It is truly accept range-free approaches, however, many challenges need to be addressed. Since there is no way to measure physical distances between nodes, existing approaches. It depend largely on connectivity-based algorithms and setting a tradeoffs between the accuracy and the number of location-equipped seed Nodes [4] needed as referees.

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II. DESIGN OBJECTIVE AND RELATED WORK

In this CDL, a Combined and Differentiated Localization method for localization that accomplish the strength of range-free approaches and range-based approaches using received signal strength indicator (RSSI).
CDL inherits the advantages of both range-free and range-based methods.

This is examined that ranging quality effect the accuracy of localization. Then to get good ranging quality, this method CDL assimilates virtual-hop localization, local filtration, and ranging-quality. To implement and evaluate CDL by real-world experiments in GreenOrbs and large-scale simulations.

It starts from a coarse-grained localization get by method such as DV-hop, and then it helps to improve the ranging quality and localization accuracy for localization process.

In general, almost all the sensor network localization algorithms share three main phases

- DISTANCE ESTIMATION
- POSITION COMPUTATION
- LOCALIZATION ALGHORITHM

The distance estimation phase involves measurement techniques to estimate the relative distance between the nodes. The Position computation consists of algorithms to calculate the coordinates of the unknown node with respect to the known anchor nodes or other neighboring nodes. The localization algorithm, calculates how the information respective distances and positions, is created in order to allow most or all of the nodes of a WSN to estimate their position. The localization algorithm may involve algorithms to reduce the errors and refine the node positions
The common methods for position calculation techniques are:

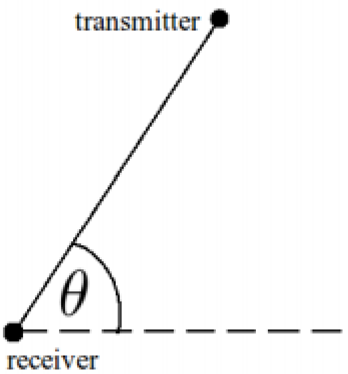
- LATERATION
- ANGULATION

RSSI finds the power of the signal of both end. First end, receiver and based on the known transmit power, the excellent loss is calculated. Next by using this we can translate this loss into a distance estimate. without any extra devices RSSI is a not costly solution, as all sensor nodes are have radios. The performance, however, is not as good as other ranging techniques due to the multipath propagation of radio signals. In [26], the authors characterize the limits of a variety of approaches to indoor localization using signal strengths from 802.11 routers.[25] They also suggest that adding additional hardware or altering the model of the environment is the only

There are four methods for measuring in distance technique:

- ANGLE OF ARRIVAL (AOA)
- TIME OF ARRIVAL (TOA)
- TIME DIFFERENT OF ARRIVAL (TDOA)
- THE RECEIVED SIGNAL STRENGH INDICATOR (RSSI)

The disperse time can be converted into distance, based on the known signal dispersion speed. These methods used with many signals, such as Radio Freq, infrared. The method DoA is impressively accurate under line-of-sight conditions.



Line-of-sight condition is difficult to meet in some environments. And the speed of sound varies in air with temp and humidity, it improves inaccuracy into distance estimation. Few signals show multi-path propagation effects that

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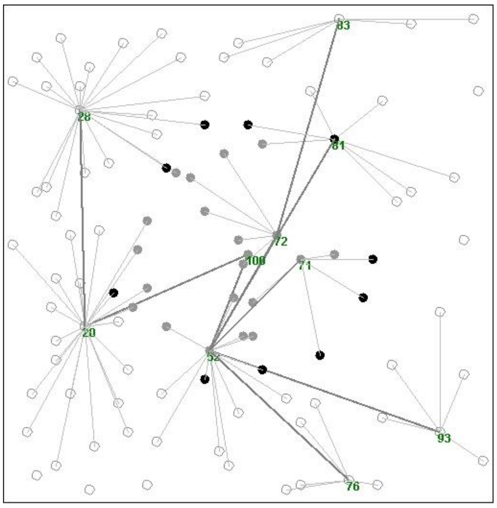
may affect the accuracy of signal detection. AoA find out the angle at which signals are received. Then these signals are use simple geometric relationships to calculate node positions. AoA provide more accurate localization result than RSSI. [25]

III. LOCALIZATION ISSUES

The first source of error in distance estimate arises from the discrete distribution of sensors. A gradient computes the shortest communication path from the source to any sensor.

- Range-based approaches measure the Euclidean distances among the nodes with various ranging techniques. These are expensive with respect to hardware, or environmental noises and dynamics.[15]
- Range-free approaches perform localization by relying only on network connectivity measurements. Therefore localization results by range-free approaches are typically imprecise and easily affected by node density.
- Non-uniform deployment of sensor nodes could affect the effectiveness of range-free localization.
- On the other side,for range-based localization, the received signal strength indicators (RSSIs) used for estimating distances is highly irregular, dynamic, and asymmetric between pairs of nodes.
- the complexity and obstacles in the forest easily affect RSSI-based range measurements, thus incurring undesired but ubiquitous errors.[16]

Many wireless sensor network-based monitoring applications are becoming feasible as fundamental data collection and network protocols are becoming efficient in handling simple sense-and-send function.[21] The computation and storage capacity of sensor nodes disperse, these nodes are capable of performing more complicated functions. So, the need to realize the complete loop of sense-control-actuate similar to the wired sensing facility demands for more in-network processing to enable any meaningful in-network actuation. One useful primitive function for many applications is edge or boundary detection of a phenomenon.



This proposes a localized edge detection algorithm using basic geometry rules and only relies on one-hop neighborhood information. This algorithm is accordingly benchmarked against one of the best localized edge detection scheme available in the public domain. Therefore we can say that the proposed algorithm readily outperformed its counterpart in dealing with both convex as well as non-convex regions while being efficient in time. The algorithm is also demonstrated to be more robust against unrelated sensor errors.

IV. SENSOR NETWORK APPLICATION

Military applications:

- Monitoring friendly forces, equipment and ammunition

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- Exploration of opposing forces and terrain
- Battlefield surveillance
- Battle damage assessment
- Nuclear, biological and chemical attack detection

Health applications:

- Tele-monitoring of human physiological data
- Tracking and monitoring patients and doctors inside a hospital
- Drug administration in hospitals

V. CONCLUSION

This paper describes overview of localization over WSN, applications, design objective, localization issues,its features and counter measures. We encourage more insight into the issues and challenges for development of solutions to the open research issues as described.

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