

# Blind Channel Gain Cartography

2016 IEEE Global Conference on Signal and Information Processing  
Greater Washington, D.C., USA  
Dec. 7<sup>th</sup> - 9<sup>th</sup>, 2016

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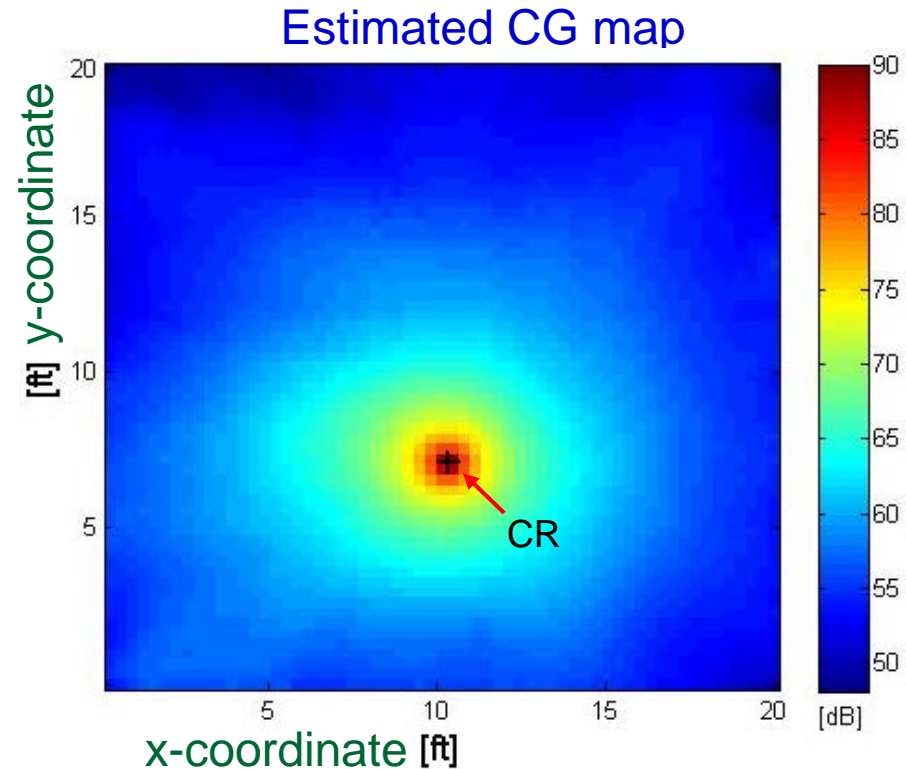
# Outline

- ❑ Channel gain (CG) cartography
- ❑ Blind CG cartography formulation
- ❑ Proposed algorithms
- ❑ Numerical results
- ❑ Conclusions and future work

# Channel gain cartography

## □ Channel gain (CG) cartography

- Global view of any-to-any CGs
- Instrumental in
  - cognitive radio (CR)
  - interference management



## □ Idea

- Spatially close radio links exhibit similar shadowing [Agrawal-Patwari'09]
- Interpolation of CG measurements between Tx-Rx pairs

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# Contributions in context

## ❑ Related work

- RF tomography using the spatial loss field (SLF) model [Patwari-Wilson'08]
- Tracking spatio-temporal dynamics of CG via KKF [Kim et al.'11]
- Experimental validation of RF tomography models [Hamilton et al.'12]
- CG cartography via low-rank and sparsity on SLF [Lee-Kim'14]

## ❑ Limitation

- Existing approaches postulate ad-hoc propagation models

## ❑ Desiderata

Joint estimation of CG map and propagation model

## ❑ Contributions

- Blind estimator for CG map and propagation function
- Efficient batch algorithm for large datasets

# Any-to-any channel gain estimation

- ❑ Sensors located at  $\mathbf{x}_n$  and  $\mathbf{x}_{n'}$  over 2-D geographical area  $\mathcal{A}$
- ❑ Channel gain (in dB) over the link  $\mathbf{x}_n - \mathbf{x}_{n'}$

$$G(\mathbf{x}_n, \mathbf{x}_{n'}) = G_0 - \gamma 10 \log_{10} \|\mathbf{x}_n - \mathbf{x}_{n'}\| - s(\mathbf{x}_n, \mathbf{x}_{n'}) \quad (1)$$

Gain at unit distance

Path-loss exponent

Shadowing

- $\|\mathbf{x}_n - \mathbf{x}_{n'}\|$ : distance between  $\mathbf{x}_n$  and  $\mathbf{x}_{n'}$

- ❑ **Goal:** Interpolation of channel gain  $G(\mathbf{x}, \mathbf{x}')$  for an **arbitrary** link  $\mathbf{x} - \mathbf{x}'$

(as)  $\{G_0, \gamma\}$  known

- **Shadowing model** allows interpolation of  $\hat{s}(\mathbf{x}, \mathbf{x}')$ 
  - Substitution of  $\hat{s}(\mathbf{x}, \mathbf{x}')$  into (1) yields  $G(\mathbf{x}, \mathbf{x}')$

# Shadowing model

- RF tomography model [Agrawal-Patwari'09]

$$s(\mathbf{x}, \mathbf{x}') = \int_{\mathcal{A}} w(\mathbf{x}, \mathbf{x}', \tilde{\mathbf{x}}) f(\tilde{\mathbf{x}}) d\tilde{\mathbf{x}} \simeq \sum_{i=1}^{N_g} w(\phi_1(\mathbf{x}, \mathbf{x}'), \phi_2(\mathbf{x}, \mathbf{x}', \tilde{\mathbf{x}}_i)) f(\tilde{\mathbf{x}}_i)$$

- Spatial loss field (SLF)  $f : \mathcal{A} \rightarrow \mathbb{R}$
- Weight function  $w$  weighs  $f(\tilde{\mathbf{x}})$  more heavily at  $\tilde{\mathbf{x}}$  lying closer to  $\mathbf{x}-\mathbf{x}'$
- $w$  functions in literature expressible in terms of

$$\left\{ \begin{array}{l} \phi_1(\mathbf{x}, \mathbf{x}') := \|\mathbf{x} - \mathbf{x}'\|_2 \\ \phi_2(\mathbf{x}, \mathbf{x}', \tilde{\mathbf{x}}) := \|\mathbf{x} - \tilde{\mathbf{x}}\|_2 + \|\tilde{\mathbf{x}} - \mathbf{x}'\|_2 \end{array} \right.$$

# Blind CG cartography

- ❑ Existing works select  $w$  heuristically
- ❑ Proposed work: joint estimation of  $f$  and  $w$ 
  - Heuristic selection of  $w$  **not** required
  - Estimation of  $w$  via kernel regression
- ❑ Problem statement
  - Given: measurements  $\{\hat{s}_t\}_{t=1}^T$  and sensor locations  $\{(\mathbf{x}_{n(t)}, \mathbf{x}_{n'(t)})\}_{t=1}^T$
  - Estimate  $\{f(\tilde{\mathbf{x}}_i)\}_{i=1}^{N_g}$  and  $w$

# Problem formulation

## □ Reproducing kernel Hilbert space

$$\mathcal{H} := \left\{ w(\boldsymbol{\phi}) = \sum_{i=1}^{\infty} \alpha_i \kappa(\boldsymbol{\phi}, \boldsymbol{\phi}_i) : \alpha_i \in \mathbb{R}; \boldsymbol{\phi}, \boldsymbol{\phi}_i \in \mathbb{R}_+^2 \right\} \leftarrow \boldsymbol{\phi} := [\phi_1, \phi_2]^T$$

- Reproducing kernel  $\kappa: \mathbb{R}^2 \times \mathbb{R}^2 \rightarrow \mathbb{R}$  e.g., Gaussian radial basis function

## □ Regularized formulation

$$(P1) \min_{\substack{w \in \mathcal{H}, \\ \mathbf{f} \in \mathbb{R}^{N_g}}} \frac{1}{T} \sum_{t=1}^T \left( \hat{s}_t - \sum_{i=1}^{N_g} w(\boldsymbol{\phi}_{t,i}) f(\tilde{\mathbf{x}}_i) \right)^2 + \mu_w \|w\|_{\mathcal{H}}^2 + \mu_f \|\mathbf{f}\|_2^2$$

- Smoothness on  $w$  promoted by  $\|w\|_{\mathcal{H}}^2 = \sum_{i=1}^{\infty} \sum_{i'=1}^{\infty} \alpha_i \alpha_{i'} \kappa(\boldsymbol{\phi}_i, \boldsymbol{\phi}_{i'})$

## □ Challenge: $\mathcal{H}$ is of possibly infinite dimension



# Finite-dimensional reformulation

□ Representer theorem [Schölkopf and Smola 02']

$$\hat{w}(\phi) = \sum_{t=1}^T \sum_{i=1}^{N_g} \alpha_{t,i} \kappa(\phi, \phi_{t,i})$$

▪ Together w/ so-called reproducing property, implies

$$\|\hat{w}\|_{\mathcal{H}}^2 = \sum_{t,t'=1}^T \sum_{i,i'=1}^{N_g} \alpha_{t,i} \alpha_{t',i'} \kappa(\phi_{t,i}, \phi_{t',i'}) = \boldsymbol{\alpha}^T \mathbf{K} \boldsymbol{\alpha}$$

□ (P1) becomes

$$(P2) \quad \min_{\boldsymbol{\alpha}, \mathbf{f}} \frac{1}{T} \|\hat{\mathbf{s}} - (\mathbf{I}_T \otimes \mathbf{f}^T) \mathbf{K} \boldsymbol{\alpha}\|_2^2 + \mu_w \boldsymbol{\alpha}^T \mathbf{K} \boldsymbol{\alpha} + \mu_f \|\mathbf{f}\|_2^2$$

# Batch algorithm

## □ Alternating minimization (AM) approach

Set  $\mu_w, \mu_f, \kappa$ , and initialize  $\mathbf{f}[0]$  at random

for  $k = 0, 1 \dots$

$$\mathbf{[S1]} \quad \boldsymbol{\alpha}[k+1] = [\mathbf{K}^T (\mathbf{I}_T \otimes \mathbf{f}[k] \mathbf{f}^T[k]) \mathbf{K} + \mu_w T \mathbf{K}]^{-1} \mathbf{K}^T (\mathbf{I}_T \otimes \mathbf{f}[k]) \hat{\mathbf{s}}$$

$$\text{Set } \mathbf{A}_{\mathbf{K}}[k] := \sum_{t=1}^T (\mathbf{e}_t \otimes \boldsymbol{\alpha}^T[k] \mathbf{K}_t^T)$$

$$\mathbf{[S2]} \quad \mathbf{f}[k+1] = (\mathbf{A}_{\mathbf{K}}^T[k] \mathbf{A}_{\mathbf{K}}[k] + \mu_f T \mathbf{I}_{N_g})^{-1} \mathbf{A}_{\mathbf{K}}^T[k] \hat{\mathbf{s}}$$

## □ Complexity can be reduced by clustering $\{\phi_{t,i}\}_{t,i}$

# Synthetic dataset

## □ Simulation setting

- 80 sensors uniformly deployed over  $\mathcal{A} = [0.5, 15.5] \times [0.5, 15.5]$
- Dataset ( $T = 3, 160$ ) generated with inverse area model [Hamilton et al' 14]

$$w(\phi_1, \phi_2) := \begin{cases} 0, & \text{if } \phi_2 > \phi_1 + \frac{\lambda}{2} \\ \min(\Omega(\phi_1, \phi_2), \Omega(\phi_1, \phi_1 + \delta)) & \text{otherwise} \end{cases}$$

where  $\Omega(\phi_1, \phi_2) := 4/\pi\phi_2\sqrt{\phi_2^2 - \phi_1^2}$ ,  $\lambda = 3.5$ , and  $\delta = 0.5$

➤ Corrupted by white Gaussian noise w/  $\sigma^2 = 10^{-3}$

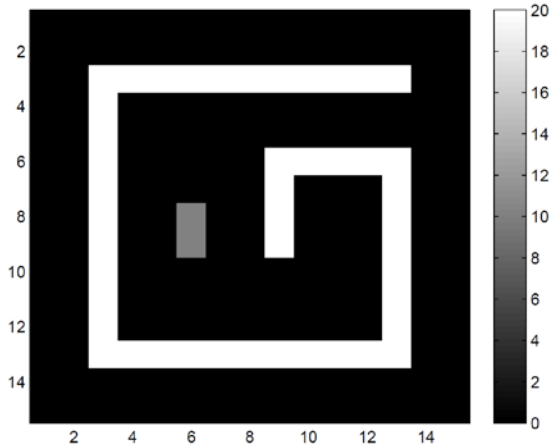
- $N_c = 1, 500$  with random sampling
- Gaussian kernel with  $\sigma_\kappa = 0.15$  adopted

$$\kappa(\phi, \phi') = \exp\left(-\frac{\|\phi - \phi'\|_2^2}{2\sigma_\kappa^2}\right)$$

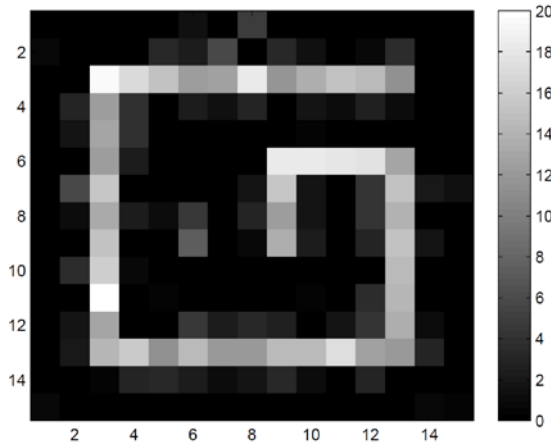
- $\mu_f = 10^{-4}$  and  $\mu_w = 0.2$

# Numerical results

True SLF

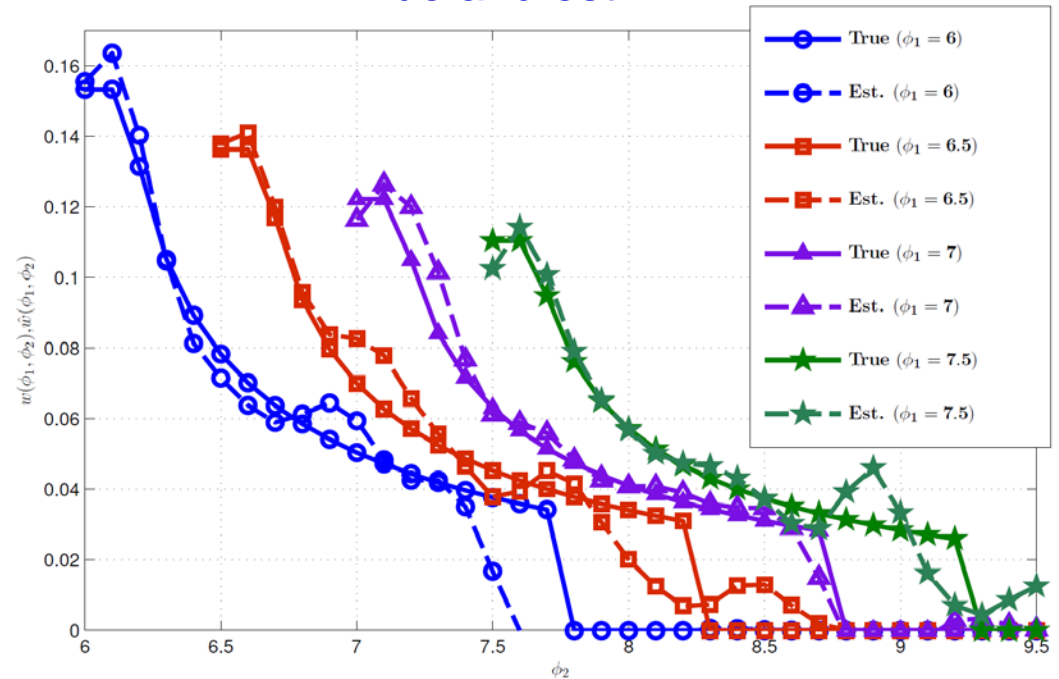


Estimated SLF



- Accurate reconstruction of the SLF
- $\hat{w}$  fits well on smooth parts of  $w$

True and est.  $w$



# Conclusions and future work

- ❑ Blind CG map estimation via nonparametric kernel regression
- ❑ Heuristics not required to select  $w$
- ❑ Clustering algorithms incorporated to reduce complexity
  
- ❑ Future work
  - Leverage prior information on  $f$
  - Real data tests

Thank You