做科研，非一朝一夕

买器材，应速战速决

Newport数千种优质产品当日发货，更多惊喜尽在PhotonSpeed™光速购！
Indoor positioning modeling by visible light communication and imaging

Jinguo Quan (权进国) 1, 2*, Bo Bai (白 静) 3, Shuang Jin (金 旷) 2, and Yan Zhang (张 安) 3

1 Key Laboratory of Network Oriented Intelligent Computation, Shenzhen Graduate School, Harbin Institute of Technology, Shenzhen 518055, China
2 Division of Information Science and Technology, Shenzhen Graduate School, Tsinghua University, Shenzhen 518055, China
3 Xi'an Electronic Engineering Research Institute, Xi'an 710100, China
* Corresponding author: quanjg@gmail.com

Received January 7, 2014; accepted March 27, 2014; posted online April 30, 2014

This letter presents a model of an indoor light positioning system (LPS) based on white LEDs and a camera. The position of an LPS receiver is determined through both its relative position to LEDs according to their images captured by the camera and LEDs’ absolute position information in the navigation frame, obtained through a visible light communication (VLC) link. The error performance of the proposed LPS is analyzed. The mean error and mean square error (MSE) of estimated receiver position using least squares (LS) and weighted least squares (WLS) estimators are both derived in the presence of non-uniform measurement bias and white Gaussian noise. The effects of communication data rate on the positioning accuracy are also studied through BER performance.

OCIS codes: 220.0220, 350.0350.

doi: 10.3788/COL201412.052201.

Currently indoor positioning with high accuracy and reliable real-time performance is in urgent need and has become one of the most exciting features of the next generation wireless systems [1, 2]. Assisted by indoor positioning systems, various location-based services can be realized. Light positioning system (LPS) with white LEDs coupled with an inexpensive imaging sensor such as embedded in a mobile handset [3, 4] is an emerging technology. It can provide concurrent indoor positioning and illumination. The light signal emitted from a modulated white LED, carrying LED’s position information, is received by an imaging sensor through a visible light communication (VLC) channel, and then the position of the imaging sensor is estimated based on the received signal’s attributes such as amplitude and angle of arrival (AOA). Meanwhile, due to a large number of small size pixels, high spatial resolution is achievable, leading to a possibly low cost and high accurate LPS. Since an LPS operates in the visible light spectrum, it does not create electromagnetic interference to existing radio frequency (RF) systems, critical for RF restricted environments.

In this letter, the LPS model with a white LED and camera is developed. Performance of a camera used as both an image sensor and a communication receiver is studied, error performance resulted from corrupted LED position information are further investigated. And the numerical results are also presented.

A typical LPS with a white LED and camera is shown below. Consider a LPS with a camera and N white LEDs mounted on the ceiling whose positions in the navigation frame are known as $\mathbf{S}_i = [X_i, Y_i, Z_i]^T$, $i=1, 2, \cdots, N$, shown in Fig. 1. The white LEDs’ image points $\mathbf{S}_i = [x_i, y_i]^T$ are captured on the image sensor with the center of the image sensor set as the origin of the relative coordinate system. The focal length of the image lens is fixed as $f$, the distance from the lens of the camera to the image sensor plane is $D$, and from the lens to the floor is $Z_C$. Let us focus on the two-dimensional (2D) position vector $\mathbf{p}_C = [X_C, Y_C]^T$ of the camera represented by the center of the image lens $\mathbf{O}$, which is the same as the position of the image sensor’s center in the navigation frame. The error performance of lease square (LS) and weighted lease square (WLS) estimators are derived and given in the following subsections, respectively.

Assume the height $Z_C$ of the camera (defined as the height of the image lens) is given. According to the homothetic triangle theory and Newton’s law of lens imaging, we can easily obtain the position of the camera $\mathbf{p}_{C,i} = [X_{C,i}, Y_{C,i}]^T$ from pairs of white LED $\mathbf{S}_i$ and its image $\mathbf{S}'_i$ on the image sensor as
\[ p_{C_i} = [X_{C_i}, Y_{C_i}]^T = [x_i + \lambda_i \cdot x_{m_i}, y_i + \lambda_i \cdot y_{m_i}]^T, \] (1)

where \( \lambda_i = \frac{z_{C_i} - z_{C0}}{D} \), and \( [x_{m_i}, y_{m_i}]^T \) is the measured position of the white LED image point \( S'_i = [x_i, y_i]^T \) on the image sensor. \( N \) values \((i = 1, 2, \cdots, N)\) obtained from \( N \) white LEDs will be identical to \( p_{C_i} = [X_{C_i}, Y_{C_i}]^T \) in the absence of noise. In the presence of measurement noise, we adopt the LS and WLS estimators to estimate \( p_{C_i} \) from \( N \) measurement results corrupted by independent Gaussian noise \( n_x = [n_{x1}, n_{x2}, \cdots, n_{xN}]^T \) and \( n_y = [n_{y1}, n_{y2}, \cdots, n_{yN}]^T \) in \( X \) and \( Y \) axes, respectively, which is mainly introduced by the imaging distortion and weak incident light. Assume \( n_x = \mu_x + v_x, n_y = \mu_y + v_y \), where \( \mu_x \) and \( \mu_y \) are the noise mean, \( v_x \) and \( v_y \) are zero mean Gaussian noise with variance \( \sigma_x^2 \) and \( \sigma_y^2 \), independent across \( N \) white LEDs. Then according to Eq. (1), the squared error is

\[ J = [x_m - (X - X_C \cdot 1) \Lambda] \cdot [x_m - (X - X_C \cdot 1) \Lambda] + [y_m - (Y - Y_C \cdot 1) \Lambda] \cdot [y_m - (Y - Y_C \cdot 1) \Lambda], \] (2)

where \( 1 \) is an \( N \times 1 \) all one vector, \( \Lambda = \text{diag}\{-\frac{1}{X} \cdots, -\frac{1}{X} \} \) is the coefficient matrix.

Differentiating (2) with respect to \( X \) and \( Y \), and setting the result to zero, we can obtain the LS estimated position as

\[ \hat{p}_C = \frac{1}{\text{tr}(A \Lambda^T)} (P \Lambda - [x_m, y_m]^T) \Lambda^T 1, \] (3)

where \( P = [X, Y]^T \) is the white LEDs’ position matrix and \( \text{tr}(\cdot) \) is the trace of a matrix. The estimation error vector is

\[ \delta p_C = p_C - \hat{p}_C = -\frac{1}{\text{tr}(A \Lambda^T)} [\delta x, \delta y]^T \Lambda^T 1. \] (4)

The mean error and the mean square error (MSE) can be easily derived as

\[ E[\delta p_C] = -\frac{1}{\text{tr}(A \Lambda^T)} \mu_x, \mu_y]^T \Lambda^T 1, \]

\[ E[(\delta X_C)^2]; (\delta Y_C)^2] = \frac{1}{\text{tr}^2(A \Lambda^T)} \left[ 1^T \Lambda \cdot \text{diag}(\sigma_x^2) \cdot \mu_x \cdot \mu_x^T \cdot \Lambda^T 1 \right. \]
\[ \left. + 1^T \Lambda \cdot \text{diag}(\sigma_y^2) \cdot \mu_y \cdot \mu_y^T \cdot \Lambda^T 1 \right]. \] (6)

The LS estimator can be improved by adopting a WLS criterion when replacing the squared error \( J \) with

\[ J = [x_m - (X - X_C \cdot 1) \Lambda]^T W_X [x_m - (X - X_C \cdot 1) \Lambda] + [y_m - (Y - Y_C \cdot 1) \Lambda]^T W_Y [y_m - (Y - Y_C \cdot 1) \Lambda], \] (7)

where \( W = \Phi^{-1} \) is the symmetric weighting matrix applicable to \( X \) and \( Y \) coordinates, \( \Phi \) is the noise correlation matrix

\[ \Phi = \mu \cdot \mu^T + \text{diag}(\sigma_1^2, \cdots, \sigma_N^2). \] (8)

Through a similar procedure, we can obtain the WLS estimated position, the WLS estimation errors, the mean error and the MSE as

\[ \hat{p}_C = \frac{1}{\text{tr}(A \Lambda W^T)} (P \Lambda - [x_m, y_m]^T) W \Lambda^T 1, \] (9)

\[ \delta p_C = p_C - \hat{p}_C = -\frac{1}{\text{tr}(A \Lambda W^T)} [\delta x, \delta y]^T W \Lambda^T 1, \] (10)

\[ E[\delta p_C] = -\frac{1}{\text{tr}(A \Lambda W^T)} [\mu_x, \mu_y]^T W \Lambda^T 1, \]

\[ E[(\delta X_C)^2]; (\delta Y_C)^2] = \frac{1}{\text{tr}(A \Lambda W^T)^2} \left[ 1^T \Lambda W \cdot \text{diag}(\sigma_x^2) \cdot \mu_x \cdot \mu_x^T \cdot \Lambda W^T 1 \right. \]
\[ \left. + 1^T \Lambda W \cdot \text{diag}(\sigma_y^2) \cdot \mu_y \cdot \mu_y^T \cdot \Lambda W^T 1 \right]. \] (12)

where \( \text{tr}(A \Lambda W^T) = 1^T A \Lambda W^T 1 \). Assume all the white LED image points have identical noise mean \( \mu_0 \) and standard deviation \( \sigma_0 \) in both \( X \) and \( Y \) axes, the weighting matrix \( W \) can be simplified from matrix \( \Phi \) to

\[ W = \mu_0^2 \cdot 1^T + \sigma_0^2 \cdot I, \] (13)

where \( \mu_0 = -\frac{1}{N} \cdot \frac{1}{N} \cdot \mu_0, \sigma_0 = \frac{1}{N} \), and \( I \) is an \( N \times N \) identity matrix. The difference between LS estimated coordinates by Eq. (3) and WLS by Eq. (9) is

\[ \hat{p}_{LS} - \hat{p}_{WLS} = \mu_0^2 (P \Lambda - [x_m, y_m]^T) \text{tr} (\Lambda) \]
\[ \cdot \left( \mu_0^2 (\Lambda W)^2 (\Lambda W)^T \right) \cdot \text{tr} (\Lambda W^T) \cdot \text{tr} (\Lambda W^T). \] (14)

When all the white LED lights are with the same height \( z_0 \), the coefficient matrix becomes \( \Lambda = -\frac{D}{z_0 - z_0} \cdot I \), and Eq. (14) reduces to \( \hat{p}_{LS} - \hat{p}_{WLS} = 0 \), which means the LS estimates have the same performance as the WLS in this special case.

With the advantage of the CMOS based camera, we can easily get access to the specific region of interest, the pixels capturing the white LED image, and obtain the incident light power of the white LED on the pixel[5,6]. The system noise that limits the performance of indoor VLC is mainly introduced by the channel and the camera. One typical noise source is the ambient light noise, and the image sensor noise of the camera[7] usually includes the dark current noise, quantum shot noise, thermal noise, amplifier noise, MOS device noise, ADC noise, and the fixed pattern noise (FPN). The ambient light noise can be easily removed using an electrical filter. Assume interference from other white LEDs and reflected light would not take a dominant role. Therefore we only consider quantum shot noise, introduced by incident light signal, ambient light noise, dark current noise, and thermal noise in calculating the system’s SNR, while all other camera noises are neglected. The system quantum shot noise variance is given by

\[ \sigma_{\text{shot}}^2 = 2e \cdot \left[ R_D (\lambda) \cdot P_I + \frac{R_D (\lambda) \cdot P_s \cdot I_d}{\text{Num}} + \frac{I_d \cdot I_s}{\text{Num}} \right] \cdot B, \] (15)

where \( e \) is the electron charge, \( R_D (\lambda) = \eta (\lambda) e \lambda / h c \) is the camera responsivity with respect to light wavelength \( \lambda \), \( I_d \) is the dark current noise, \( I_s = 0.562 \) is the noise bandwidth factor, \( B \) is the channel bandwidth, Num is the total pixel number of the image sensor, \( P_s \) is the total received ambient light noise.

The equivalent system noise is a Gaussian noise with a
For on-off keying (OOK) modulation scheme, where noise and thermal noise total variance that is the sum of contributions from shot noise, and thermal noise:

\[ \sigma_{total}^2 = \sigma_{shot}^2 + \sigma_{thermal}^2. \]  

(16)

The system SNR can be expressed as

\[ \text{SNR} = \frac{(R_D \cdot P_t)^2}{\sigma_{total}^2} = \frac{(R_D \cdot P_t)^2}{\sigma_{shot}^2 + \sigma_{thermal}^2}. \]

(17)

The communication BER is given by

\[ Q(x) = \int_{-\infty}^{+\infty} e^{-y^2/2} dy. \]

With the interference of the VLC channel noise or camera noise, LED position information may be misinterpreted randomly at the image sensor. So when the position information of only one LED is incorrectly interpreted, the mean error and the MSE are

\[ \mu_{in} = \sum_{i=1}^{N} \alpha_i \sum_{j=1 \neq j'}^{N} \beta_{ij} \cdot (X_j - X_i), \]

(18)

and

\[ \sigma_{in}^2 = \sum_{i=1}^{N} \alpha_i \sum_{j=1 \neq j'}^{N} \beta_{ij} \cdot (X_j - X_i)^2, \]

(19)

where \( \alpha_i \) is the probability that the position information transmission of the \( i \)th white LED, among all \( N \) LEDs, will have an error, and \( \beta_{ij} \) is the probability for the position information of the \( i \)th white LED to be misinterpreted as the one for the \( j \)th white LED. To simplify the computation, set the probabilities \( \alpha_i = 1/N \) and \( \beta_{ij} = 1/(N-1) \), and considering all possible cases with incorrectly decoded LED position information, from LED 1 to LED \( N \), the total mean error and MSE are

\[ \mu_{total} = \sum_{k=1}^{N} k \cdot \mu_{in} \cdot C_N^k \cdot (1 - P_e)^{N-k} \cdot P_e^k = 0, \]

(20)

and

\[ \sigma_{total}^2 = \sum_{k=1}^{N} k \sigma_{in}^2 C_N^k (1 - P_e)^{N-k} P_e^k = \frac{1}{N\cdot(N-1)} \sum_{i=1}^{N} \sum_{j=1 \neq j'}^{N} (X_j - X_i)^2 \sum_{k=1}^{N} k C_N^k (1 - P_e)^{N-k} P_e^k, \]

(21)

where \( P_e \) is the decoding error probability of a VLC link from a white LED to the receiver, namely the BER.

In this section, we evaluate the performance of both the LS and WLS estimators for the LPS with white LEDs and camera, and examine the accuracy of the derived analytical results. We adopt the mean error (bias), root mean square error (RMSE) and the variance of the positioning algorithms as performance metrics:

\[ \text{Bias} = \sqrt{\text{E}[\delta X_C]^2} + \sqrt{\text{E}[\delta Y_C]^2}, \]

(22)

\[ \text{RMSE} = \sqrt{\text{E}[(\delta X_C)^2] + \text{E}[(\delta Y_C)^2]}, \]

(23)

\[ \text{VAR} = \text{var}^2(X_C) + \text{var}^2(Y_C), \]

(24)

and examine the effects of different parameters on estimator performance, in particular measurement noise bias \( \mu \) and additive Gaussian noise standard deviation \( \sigma \). Also the positioning error resulting from VLC link is evaluated with respect to the communication data rate. All the numerical results are the sample averages of \( 10^4 \) independent realizations. The distribution of white LEDs and camera (in meters) is shown in Fig. 2. To simplify the simulation, we assume every LED image has the same standard deviation in both \( X \) and \( Y \) axes, and Table 1 gives the related parameters.

Set the noise mean for each LED image as 10% of its distance to the image sensor origin. Figures 3 and 4 show the bias and RMSE performance of the LS and WLS estimators with estimated LED position against the white noise standard deviation \( \sigma \), respectively. The standard deviation takes values from 0 to 25 mm with a step size 1 mm, and the communication data rate in Fig. 4 is 500 kbps. The variance performance of LS and WLS estimators for LPS with estimated LED positions against the white noise standard deviation \( \sigma \) is compared in Fig. 5. Not surprisingly, the variance performance of LS estimator with measurement bias is worse than the WLS estimator, and there exists a big gap between the CRLB\(^9\) for either the LS or the WLS estimator with

![Fig. 2. Distribution of white LEDs and a camera.](image)

Table 1. Related Parameters

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Quantity</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>( P_s )</td>
<td>White LED Light Power</td>
<td>20 mW</td>
</tr>
<tr>
<td>( \Phi_{1/2} )</td>
<td>Semi-angle at Half Power</td>
<td>60 deg</td>
</tr>
<tr>
<td>( P_b )</td>
<td>Average Ambient Light Power</td>
<td>60 ( \mu )W</td>
</tr>
<tr>
<td>( R_D )</td>
<td>Camera Responsivity</td>
<td>0.21 A/W</td>
</tr>
<tr>
<td>( T_K )</td>
<td>Absolute Temperature</td>
<td>295 K</td>
</tr>
<tr>
<td>( g_m )</td>
<td>FET Transconductance</td>
<td>30 mS</td>
</tr>
<tr>
<td>( \Gamma )</td>
<td>FET Channel Noise Factor</td>
<td>1.5</td>
</tr>
<tr>
<td>( I_2 )</td>
<td>Noise Bandwidth Factor ( I_2 )</td>
<td>0.562</td>
</tr>
<tr>
<td>( I_3 )</td>
<td>Noise Bandwidth Factor ( I_3 )</td>
<td>0.0868</td>
</tr>
<tr>
<td>( H )</td>
<td>Fixed Capacitance</td>
<td>112 pF/cm(^2)</td>
</tr>
<tr>
<td>( I_d )</td>
<td>Dark Current</td>
<td>20 nA</td>
</tr>
<tr>
<td>( D )</td>
<td>Image Distance</td>
<td>25 mm</td>
</tr>
<tr>
<td>( \text{Num} )</td>
<td>Total Pixel Numbers</td>
<td>1024×1024</td>
</tr>
</tbody>
</table>
measurement bias. Performance against VLC system BERs, resulted from different communication data rate from 800 kbps to 1.4 mbps with a step of 50 kbps, is given in Fig. 6. The mean of imaging noise is 10% to the image sensor origin, and deviation $\sigma$ is fixed as 10 mm. It shows that the RMSE error dramatically increases when the system BER grows, and the RMSE performance of WLS estimator is firstly much better than the LS estimator.

In conclusion, this letter presents an indoor LPS model using white LEDs and a camera, and corresponding LS and WLS position estimation algorithms. The mean error and MSE of the LS and WLS estimators are both derived, which show a better performance of the WLS estimator with estimated LED positions. The effects of VLC error on the estimator performance and relevant communication parameters like data rate are also studied. The analytical and simulation results match well.

This work was supported by the program ‘Technology and applications of the visible light communication with LEDs’ and the program ‘Application study for the LED informationization technology’, both of them are financially supported by the Shenzhen government.

Fig. 3. Performance of LPS with known LED positions. (a) Bias; (b) RMSE

Fig. 4. Performance of LPS with estimated LED positions. (a) Bias; (b) RMSE

Fig. 5. Variance performance with estimated LED positions. (a) With measurement bias; (b) without measurement bias

Fig. 6. RMSE performance of LPS versus system BERs.

References