



## Description

System and Method for Estimating a Location of a Local Device  
and a Local Device

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The present invention relates to a method for estimating a location of a local device and a related system for estimating a location of a local device and the local device.

10 Outdoor location systems are ubiquitous, e.g. in navigation systems of cars, phones and even watches. One of these location systems is the global navigation satellite system. This system is based on a time of arrival approach. The satellites have precisely synchronized clocks. Each  
15 satellite regularly broadcasts a signal stamped with a global time. The signals are arriving at the local device at different local times due to the differently long distances from the satellites to the local device. The local device determines based on the time differences the relative  
20 distances to the satellites and by means of trilateration its actual location.

These systems strongly depend on a clear line of sight. Obstacles may alter the travelling speed of the signals,  
25 provide echoes, etc. Therefore, the global navigation system is not reliable indoors.

An approach to provide an indoor geolocation system is given in "Algorithm for TOA-based indoor geolocation" published by  
30 M. Kanaan and K. Pahlavan in Electronics Letters, vol. 40, no. 22, October 28, 2004. The geolocation system is based on a time of arrival approach. The expected time of arrival from certain points is known. The system determines an estimated location based on a search for a minimal difference  
35 of a measured time of arrival and the expected time of arrival from the certain points.

The present invention provides an alternative approach for an indoor geolocation system and a method for estimating a location of a local device which may avoid the use of synchronized clocks.

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According to one aspect of the invention a method for estimating a location of a local device comprises the following steps:

10 broadcasting a signal between at least one beacon and the local device;  
determining a time of flight value of each of the signals at a location of the local device for obtaining an actual set of time of flight values;  
estimating the location of the local device based on the  
15 actual set of time of flight values and at least one reference set of time of flight values each reference set corresponding to a known location of the local device.

20 According to a second aspect of the invention a system for estimating a location of a local device comprises:  
at least one beacon each emitting a signal upon a trigger signal;  
a local device having a trigger generator for emitting the trigger signal, a threshold sensor for detecting a first rise  
25 of the signal emitted by one of the beacons above a threshold, and a timer connected to the trigger generator and the threshold sensor for determining a time of flight value between the one of the beacons and the local device at a location;  
30 a storage unit storing at least one reference set of time of flight values each reference set corresponding to a known location of the local device; and  
an estimation means for estimating the location of the local device based on the actual set of time of flight values  
35 determined by the timer and the at least one reference set of time of flight values.

According to a third aspect of the invention a local device for performing a method according to the first aspect comprises:

a trigger generator for emitting a trigger signal, a  
5 threshold sensor for detecting a first rise above a threshold of a signal emitted by a beacon upon receipt of the trigger signal, and a timer connected to the trigger generator and the threshold sensor for determining a time of flight value between the beacon and the local device at a location;  
10 a memory device storing at least one reference set of time of flight values each reference set corresponding to a known location of the local device; and  
an estimation means for estimating the location of the local device based on the actual set of time of flight values  
15 determined by the timer and the at least one reference set of time of flight values.

According to a fourth aspect a system for estimating a location of a local device comprises:

20 a local device emitting a signal upon a trigger signal;  
at least one beacon having a trigger generator for emitting the trigger signal, a threshold sensor for detecting a first rise of the signal emitted by the local device above a threshold, and a timer connected to the trigger generator and  
25 the threshold sensor for determining a time of flight value between the one of the beacons and the local device at a location;  
a memory device storing at least one reference set of time of flight values each reference set corresponding to a known  
30 location of the local device; and  
an estimation means for estimating the location of the local device based on the actual set of time of flight values determined by the timer and the at least one reference set of  
time of flight values.

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The present invention will be illustrated taking reference to embodiments and figures. The figures:

Figure 1 illustrates a set up for a first embodiment;

Figure 2 illustrates a block diagram of a local device according to the first embodiment;

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Figure 3 illustrates a block diagram of a beacon according to the first embodiment;

Figure 4 illustrates a flow diagram according to the first embodiment; and

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Figure 5 illustrates a block diagram of an estimation means according to the first embodiment.

15 A set up of the first embodiment is demonstrated for an exemplary surrounding. A floor plan of an apartment having several rooms and respective doors is illustrated in figure 1. A plurality of beacons 1 is arranged in some or all of the rooms. Two or more beacons 1 may be arranged in one

20 room, in particular in larger rooms. The beacons 1 are stationary at well defined positions.

A person moving in the apartment carries a local device 2. The local device 2 and the beacons 1 do interact such that a

25 location of the local device 2 may be determined or estimated and provided to the person.

The estimation of the location of the local device 2 is based on time of flight measurements.

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Firstly, the time of flight value depends on the shortest distance of the local device 2 to the selected beacon 1. The relation of the time of flight value and the shortest distance is determined by the travelling speed of the signal.

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There may be, however, a plurality of travelling paths of a signal between the local device 2 and the selected beacon 1. Reflections of the signal at obstacles 5, like doors, walls,

metallic objects, etc. are causing alternative travelling paths 6 additional to a travelling path 4 along the shortest distance. A fraction of the signal travelling along an alternative travelling path 6 is always arriving later at the beacons 1 and the local device 2 compared to a fraction of the signal travelling along the shortest distance. Therefore, at a first glance a time of flight measurement should reflect the shortest distance 4 between the beacons 1 and the local device 2.

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On closer inspection there may be situations in which a time of flight measurement reflects a distance corresponding to an alternative travelling path 6. The following demonstration is only given as an example and is not intended to cover fully all technical limitations and physical effects causing the above situation.

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A signal is dampened by absorbers, like walls, doors, non-metallic objects etc, placed along a travelling path. The signal along the shortest distance 4 is dampened by two walls in the exemplary situation of figure 1. The signal along the alternative travelling path 6 is dampened by another wall and maybe damped by two doors which can be opened or closed individually.

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For illustration purpose a signal travelling through two walls or two doors is assumed to be just damped below a detection limit of receiving units in the local device 2 and the beacon 1, respectively. A signal travelling along the shortest path 4 is not detected. Hence, a time of flight measurement performed by the beacon 1 and the local device 2 does not reflect the shortest path 4.

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In a first situation both doors may be open along the alternative travelling path 6. The signal strength remains above the detection limit. A time of flight measurement performed may reflect the longer distance according to the

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alternative travelling path 6 as no measurement corresponding to the shortest distance 4 could be obtained.

In a second situation one of the doors may be closed. The  
5 signal strength of the signal along the alternative path 6 is  
dropped below the detection limit, too. A signal travelling  
along a second alternative path 6' may now provide the only  
signal above the detection limit. Thus, a different time of  
flight value is obtained just by closing one door and without  
10 a change of the location of the local device 2.

A movement of the local device 2 along a direction 17 may  
provide a discontinuous increase or decrease of time of  
flight values. Considering again the exemplary situation  
15 given in figure 1, the local device 2 may be moved to a  
further location 2' where no obstacle is in the line of sight  
18 between the local device 2 and the beacon 1. As long as  
two walls obstruct the line of sight, only the signal  
travelling along an alternative travelling path 6' provides a  
20 sufficient signal strength. At a moment, a free line of  
sight is established, the signal strength of a signal  
travelling along the shortest distance 18 rises above the  
detection limit. At this moment, the time of flight values  
measured drop from a larger time of flight value  
25 corresponding to the alternative travelling path 6' down to a  
lower time of flight value corresponding to the shortest  
distance 18. This discontinuity of the time of flight values  
measured reflects the discontinuity caused by the detection  
limit of sensors used.

30 A first embodiment of a method for estimating the location of  
the local device may deal with above situations. A brief  
description of a local device 2 and a beacon 1 according to a  
first embodiment is given which may be used for a method to  
35 estimate the location of the local device 2.

The local device 2 according to the first embodiment  
comprises a timer 3, a trigger generator 4, an emitter 5, a

receiver 6, a threshold sensor 7, and an estimation means 8. The trigger generator 4 generates a trigger signal 10 which is synchronously forwarded to the timer 3 and the emitter 5. The timer 3 is reset and started by the trigger signal 10.

5 The emitter 5 broadcasts the trigger signal 10. The trigger signal 10 may be encoded such that it addresses a single specified beacon 1. The trigger signal 10 may be encoded by a unique sequence of pulses or by a unique carrier frequency, for instance.

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The receiver 6 receives a signal 11 broadcasted by the beacon 1. The signal 11 is forwarded to the threshold sensor 7. The threshold sensor 7 outputs a stop signal 12 at the moment the incoming signal 11 rises above a threshold value. The stop signal 12 is forwarded to the timer 3 such that the timer 3 is stopped. The timer 3 transmits the measured duration, i.e. the value of the time interval between the trigger signal 10 and the stop signal 12, to an estimation means 8.

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Each beacon 1 may encode a unique signature into the signal. Therefore, a signal decoder 13 and a verification device 14 may be provided in the local device 2. The incoming signal 11 is provided to the signal decoder 13. The signal decoder 13 decodes the incoming signal 11 and determines the beacon 1 which broadcasted the incoming signal 11. The verification device 14 verifies that the incoming signal 11 corresponds to the same beacon 1 which has previously been addressed by the trigger signal 10. If so the verification device 14 confirms the measured duration with an approval signal 15 sent to the estimation means 8.

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The signal decoder 13 may be activated by the stop signal 12.

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The beacon 1 according to the first embodiment comprises a receiver 20, a threshold detector 21, a trigger decoder 22, a signal generator 23, and an emitter 24 (figure 3). The receiver 20 may receive an incoming trigger signal 25 which

has been previously emitted by the local device 2. The optional threshold detector 21 outputs an activation signal 26 when the incoming trigger signal 25 exceeds a threshold value. The trigger decoder 22 may be activated by the  
5 activation signal 26. The trigger decoder 22 decodes the incoming trigger signal 25 and determines whether the beacon 1 is addressed by the incoming trigger signal 25. If so the signal generator 23 is activated for generating a signal 27. The signal 27 may be provided with a signature which is  
10 unique for each of the beacons 1 used. The signal 27 is broadcasted by the emitter 24.

The first embodiment of a method for estimating the location is explained along with a flow diagram in figure 4.

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The local device 2 generates a trigger signal 10 by means of its trigger generator 4. The timer 3 is started. The trigger signal 10 is encoded to address a specific one of the beacons 1 and emitted by the emitter 5 (step 101).

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The trigger signal 10 travels along a plurality of travelling paths 4, 6 to the beacons 1. Each of the beacons 1 receives a trigger signal 25 being part of the emitted trigger signal 10. The trigger signal 10 may be damped, distorted, provided  
25 with several echoes, etc.

The beacon 1 addressed by the trigger signal 25 returns a signal 27 upon receipt of the trigger signal 10 (step 102). There may be a delay of processing the trigger signal 10 and  
30 generating the signal 27 by means of the signal generator 23.

The signal 27 travels along a plurality of travelling paths 4, 6 to the local device 2. The local device 2 receives an incoming signal 11 being part of the emitted signal 27. The  
35 incoming signal 11 may be damped, distorted, provided with several echoes, etc.

The threshold sensor 7 stops the timer 3 when the signal strength of the incoming signal 11 rises above a predetermined threshold value (step 103). The duration measured by the timer 3 is forwarded to the estimation means 8 (step 104). The estimation means 8 stores the duration and interprets the duration as a time of flight value of the signal 27 between the local device 2 and the beacon 1 addressed by the trigger signal 10.

Several time of flight values are gathered for the same beacon 1 by repeating steps 101 to 104 several times (loop 105). An average value for the several time of flight values is obtained using a Gaussian filter (step 110). A histogram of the time of flight values may be determined and a Gaussian distribution is fitted to the histogram. The mean value of the Gaussian distribution may be taken as average of the time of flight values. The average value is stored in a first memory 30 of the estimation means 8 (figure 5).

Other beacons 1 are addressed in sequence by means of differently encoded trigger signals 10 (loop 111). An average time of flight value is obtained for each of the other beacons 1 and stored in the first memory 30 as outlined above along with steps 101 to 110. Some beacons 1 may not respond because the trigger signal 10 or the signal 27 is dampened below detection limits of the receivers 6, 25. Preferably, the sequence is repeated until at least average time of flight values corresponding to three different beacons 1 could be obtained.

A map of the area in which the local device 2 may move is stored in a second memory 31 of the estimation means 8. The map contains a reference set, so-called fingerprints, for some reference locations in the area. Each fingerprint comprises a set of time of flight values the local device 10 would determine at the reference location. The fingerprints may be obtained during a training by moving the local device 10 to the reference locations and determining average time of

flight values as outlined above taking reference to steps 101 to 110. The average time of flight values are stored in the second memory 31.

5 Movable objects in the area may be moved into different positions. The movable objects may affect the time of flight values. Thus, an embodiment provides additional fingerprints for at least some of the locations for which the movable objects are arranged in different positions. The additional  
10 fingerprints are stored in the second memory 31. Thus, the map may contain several fingerprints for a single location. The map may contain additional to the location information additional information referring to the position of movable objects in the area. The movable objects may be doors,  
15 movable walls, furniture, vehicles, robots, parts of machines etc.

The estimation means 8 estimates the location of the local device 2 using a predictor means 32. The predictor means 32  
20 loads the set of reference values, i.e. the map of fingerprints, and applies a prediction algorithm to the reference set and the actual average flight of time values stored in the first memory 31.

25 The prediction algorithms may use neural networks, adaptive filters, or a maximum likelihood estimation. An underlying concept of some of the prediction algorithms is to determine the difference of the actual value and each reference value and to sum up the reference locations weighted by the  
30 difference. The estimated location is taken for the weighted sum.

In a second embodiment the trigger signal 10 may be not encoded, but addresses all beacons 1 simultaneously. The  
35 threshold sensor 7 emits a release signal 12 when the incoming signal 11 caused by a beacon 1 rises above the threshold value. The timer 3 forwards the duration between the trigger signal and the release signal 12 to the

estimation means 8 but the timer 3 is not reset or stopped. Thus, the timer 3 may forward the duration value between the trigger signal and a further release signal 12 caused by a further beacon 1. The signal decoder 13 decodes a signature  
5 of the emitting beacon 1 in the incoming signal 11. The verification device 14 may confirm based on the signature that the incoming signal 11 is of beacon selected of a specified group of beacons 1. The verification device 14 forwards a signal 15 to the estimation means 8. The signal  
10 15 may be encoded with a canceling information such that the estimation means 8 clears a previously obtained duration value from the first memory 31. Or the signal 15 may be encoded to forward the signature of the beacon 1 such that the estimation means 8 can store the signature of the beacon  
15 1 along with the previously obtained duration value.

In a third embodiment the timer 3 is not triggered by the threshold sensor 7 but by the validation means 14. The duration measured by the timer 3 thus includes the processing  
20 time of the decoder 13. The map of fingerprints should be obtained by the same local device 2 or an equally configured device which will be used in the area. Therefore, the map may account for the processing time of the decoder 13.

25 In a fourth embodiment standard WLAN transmitter devices may be used for the local device 2 and the beacons 1. The WLAN transmitter device can be reconfigured to provide the timer 3, the trigger generator 4, the emitter 5, the receiver 6, and the threshold sensor 7. Equally a WLAN transmitter  
30 device can be reconfigured to provide the receiver 20, the threshold detector 21, the trigger decoder 22, the signal generator 23, and the emitter 24. Other standard devices like RFID-transmitters, UMTS-transmitters, GSM-transmitters, WiMaX-transmitters, UWB-transmitters, bluetooth-transmitters  
35 may be reconfigured to be used in a local device 2 and a beacon 1.

The estimation means 8 may be arranged in one of the beacons 1 or a separate device instead being placed on the local device 2. The duration measured by the timer 3, i.e. the time of flight values can be broadcasted to the estimation means via the emitter 5 or a separate emitter. The estimation means 8 estimates the location of the local device 2 and forward the estimated location via a broadcast signal to the local device 2.

10 The local device 2 may be provided with a display for indicating the estimated location.

In a fifth embodiment the beacons 1 comprise a timer 3, a trigger generator 4, an emitter 5, a receiver 6, and a threshold sensor 7. The local device 2 comprises a receiver 20, a threshold detector 21, a trigger decoder 22, a signal generator 23, and an emitter 24. Hence, the beacons 1 emit the trigger signal 10 and the local device 2 returns a signal 27 upon receipt of the trigger signal 10. The time of flight values measured by the beacons 1 are forwarded to an estimation means 8. The estimation means 8 performs a location estimation as outlined along with the above embodiments.

## Claims

1. A method for estimating a location of a local device, comprising the steps of:

- 5 - broadcasting a signal between at least one beacon (1) and a local device at a location;
- determining a time of flight value of each of the signals for obtaining an actual set of time of flight values;
- 10 - estimating the location of the local device (2) based on the actual set of time of flight values and at least one reference set of time of flight values each reference set corresponding to a known location of the local device (2).

2. The method according to claim 1, wherein each of the time  
15 of flight values is determined as a time interval starting when one of the local device (2) and the beacons (1) triggers an other one of the local device (2) and the beacons (1) and ending when the one of the local device (2) and the beacons (1) detects a first rise above a threshold value of the  
20 intensity of the signal emitted by the other one of the local device (2) and the beacons (1).

3. The method according to claim 2, wherein at least one of the time of flight values is determined as expectation value  
25 of a normal distribution fitted to a plurality of time intervals determined for one beacon and at one location of the local device (2).

4. The method according to one of the claims 1 to 3, wherein  
30 the at least one reference set is obtained by placing the local device (2) at one of the known locations, determining the actual set of time of flight values, and storing the actual set of time of flight values as reference set of time of flight values for the known location.

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5. The method according to one of the claims 1 to 4, wherein the location of the local device (2) is estimated by weighting each known location corresponding to one of the

reference sets with a difference of the one reference set to the actual set.

6. A system for estimating a location of a local device (2),  
5 comprising:

- at least one beacon (1) each emitting a signal upon a trigger signal (10);

- a local device (2) having a trigger generator (4) for emitting the trigger signal (10), a threshold sensor (7) for  
10 detecting a first rise of the signal emitted by one of the beacons (1) above a threshold, and a timer (3) connected to the trigger generator (4) and the threshold sensor (7) for determining a time of flight value between the one of the beacons (1) and the local device (2) at a location;

15 - a memory device (31) storing at least one reference set of time of flight values each reference set corresponding to a known location of the local device (2); and

- an estimation means (8) for estimating the location of the local device (2) based on the actual set of time of flight  
20 values for the local device (2) at the location and the at least one reference set of time of flight values.

7. The system according to claim 6, the local device (2) comprising a radio transmitter for transmitting the actual  
25 set of time of flight values to the estimation means (8) and a receiver for receiving the estimated location.

8. The system according to claim 6 or 7, wherein the beacon (1) is at least one of WLAN-transmitter, RFID-transmitter,  
30 GSM-transmitter, UMTS-transmitter, and WiMaX-transmitter.

9. A local device for performing a method according to claims 1 to 5, comprising:

- a trigger generator (4) for emitting a trigger signal (10),  
35 a threshold sensor (7) for detecting a first rise above a threshold of a signal emitted by a beacon (1) upon receipt of the trigger signal (10), and a timer (3) connected to the trigger generator (4) and the threshold sensor (7) for

determining a time of flight value between the beacon (1) and the local device (2) at a location;

- a memory device (31) storing at least one reference set of time of flight values each reference set corresponding to a known location of the local device (2); and

- an estimation means (8) for estimating the location of the local device (2) based on the actual set of time of flight values determined by the timer (3) and the at least one reference set of time of flight values.

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10. A system for estimating a location of a local device (2), comprising:

- a local device (2) emitting a signal upon a trigger signal (10);

- at least one beacon (1) having a trigger generator (4) for emitting the trigger signal (10), a threshold sensor (7) for detecting a first rise of the signal emitted by the local device (2) above a threshold, and a timer (3) connected to the trigger generator (4) and the threshold sensor (7) for

determining a time of flight value between the one of the beacons (1) and the local device (2) at a location;

- a memory device (31) storing at least one reference set of time of flight values each reference set corresponding to a known location of the local device (2); and

- an estimation means (8) for estimating the location of the local device (2) based on the actual set of time of flight values determined by the timer (3) and the at least one reference set of time of flight values.

FIG 1

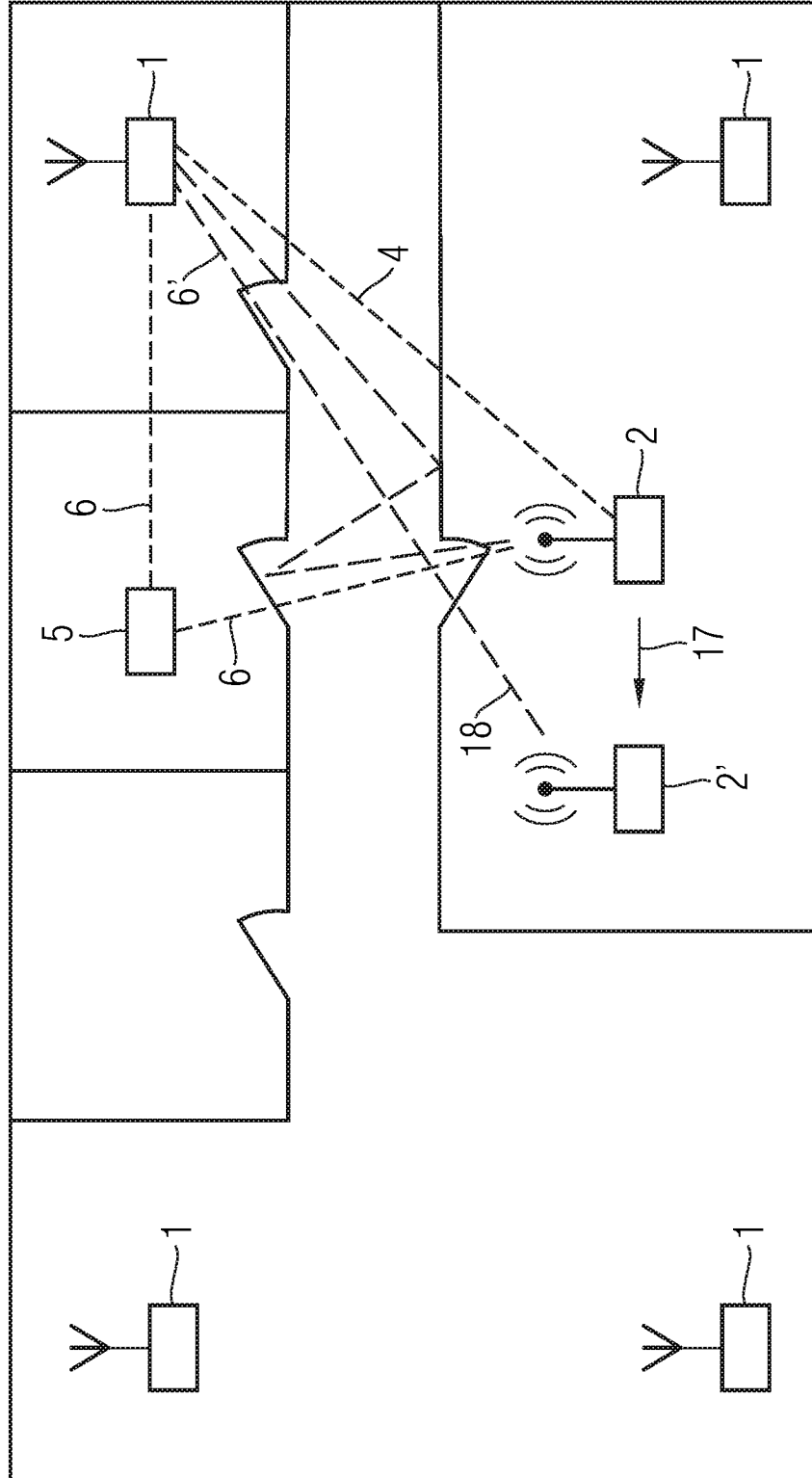


FIG 2

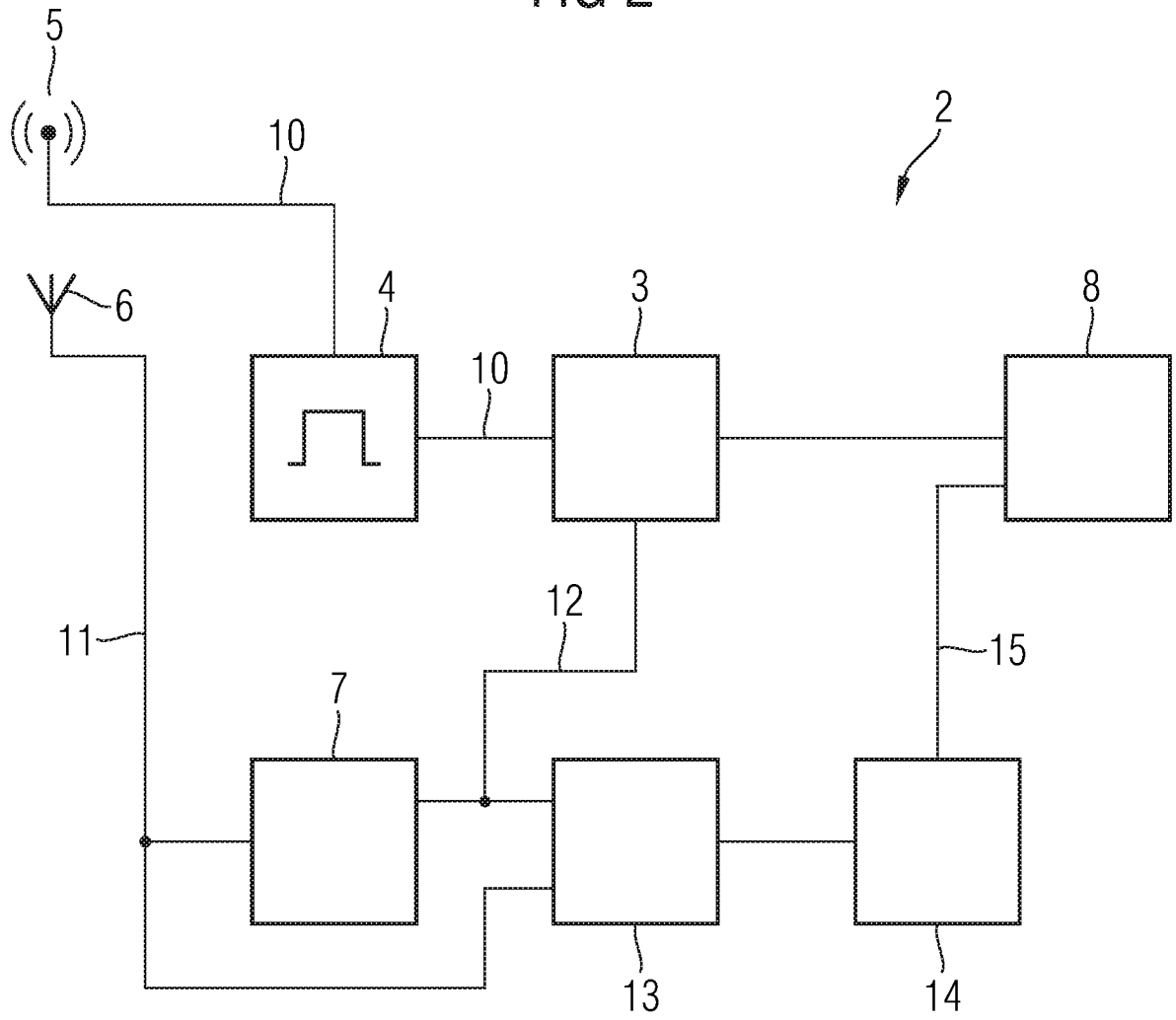


FIG 3

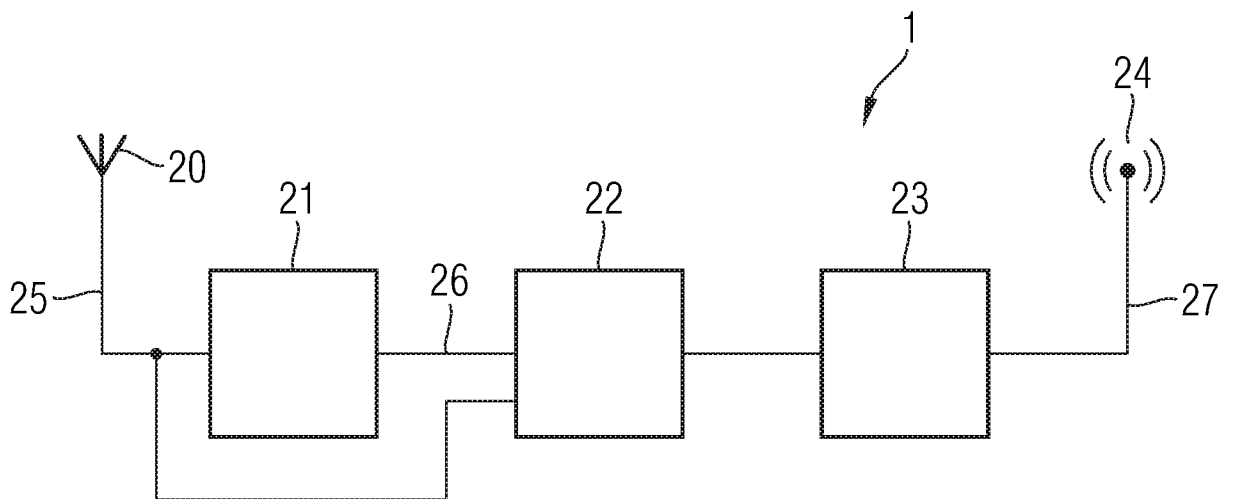


FIG 4

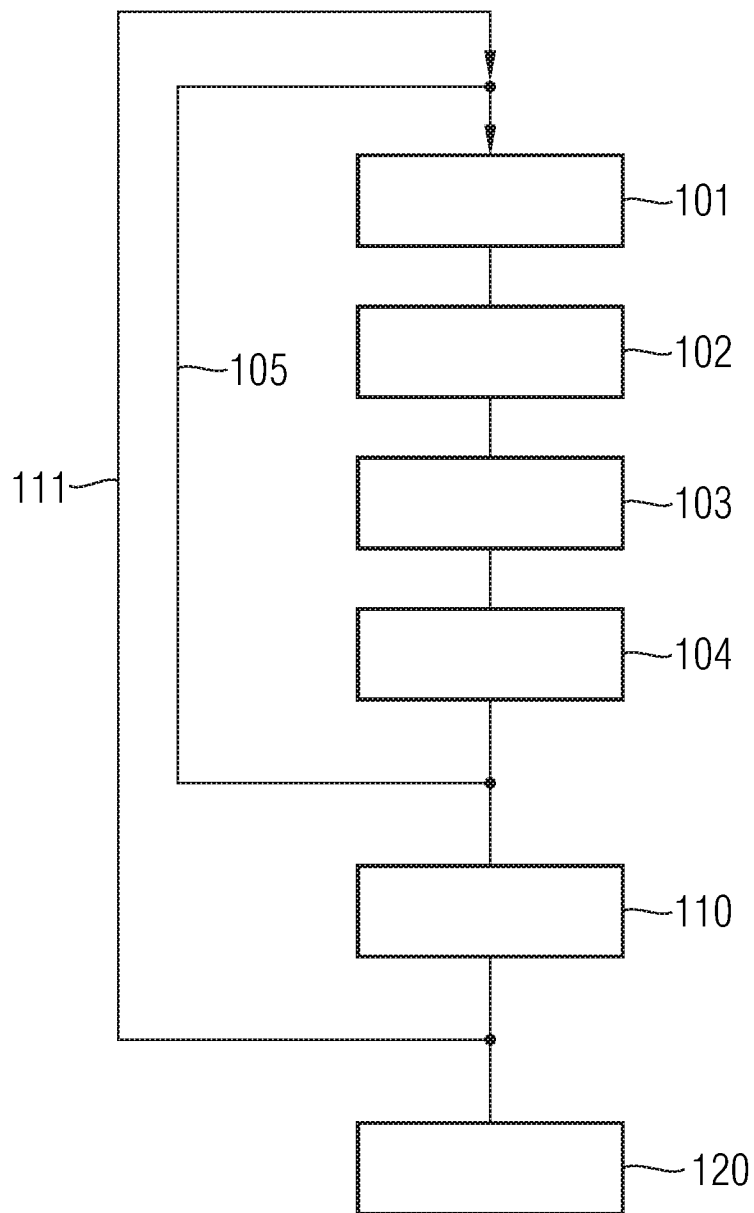


FIG 5

