Design and Performance Evaluation on Ultra-Wideband Time-Of-Arrival 3D Tracking System

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Abstract

A three-dimensional (3D) Ultra-Wideband (UWB) Time--of-Arrival (TOA) tracking system has been studied at NASA Johnson Space Center (JSC) to provide the tracking capability inside the International Space Station (ISS) modules for various applications. One of applications is to locate and report the location where crew experienced possible high level of carbon-dioxide and felt upset. In order to accurately locate those places in a multipath intensive environment like ISS modules, it requires a robust real-time location system (RTLS) which can provide the required accuracy and update rate. A 3D UWB TOA tracking system with two-way ranging has been proposed and studied. The designed system will be tested in the Wireless Habitat Testbed which simulates the ISS module environment. In this presentation, we discuss the 3D TOA tracking algorithm and the performance evaluation based on different tracking baseline configurations. The simulation results show that two configurations of the tracking baseline are feasible. With 100 picoseconds standard deviation (STD) of TOA estimates, the average tracking error 0.2392 feet (about 7 centimeters) can be achieved for configuration “Twisted Rectangle” while the average tracking error 0.9183 feet (about 28 centimeters) can be achieved for configuration “Slightly-Twisted Top Rectangle”. The tracking accuracy can be further improved with the improvement of the STD of TOA estimates. With 10 picoseconds STD of TOA estimates, the average tracking error 0.0239 feet (less than 1 centimeter) can be achieved for configuration “Twisted Rectangle”.

References

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UWB Systems Group / EV4
Avionic Systems Division (EV)

NASA Johnson Space Center
“No one can whistle a symphony. It takes a whole orchestra to play it.”

– H.E. Luccock
UWB Systems Group
(A Functional Team Architecture)

Analysis Team
- Algorithm Development
- System Simulation
- Performance Evaluation
- Proposal Development
  - David Ni
  - Dickey Arndt
  - Brian Bourgeois
  - Richard Barton

Hardware Team
- Hardware Design
- System Testing
- Product Investigation
  - Phong Ngo
  - Chau Phan
  - John Dusl

Software Team
- Software Development
- Software Maintenance
  - David Ni
  - Kent Dekome
  - Julia Gross

Administrative Liaison
- Internal Networking
- External Networking
- Funding Channel
- Order and Purchase
  - Dickey Arndt
  - Phong Ngo
  - Chau Phan
  - Julia Gross
  - John Dusl
Outline

- UWB Technology Development at JSC
- Motivation of Work
- UWB Fine Time Resolution
- TOA Tracking Methodology and Algorithm
- TOA Simulation Results
- Summary
- Future Work
UWB AOA Long Range Tracking

- UWB AOA long range tracking with the SCOUT vehicle at the Meteor Crater, Arizona in 2005 and 2006
- Excellent tracking performance with less than 1% error at ranges up to 4000 ft
- No RF interference with on-board GPS, video, audio, and telemetry systems
Use Time Difference of Arrival (TDOA) technique to provide sub-inch tracking resolution

Two tracking points on target to accurately guide the target into its docking station
UWB TDOA 3D High Resolution Tracking for Robotic Control

- UWB TDOA 3D tracking at Honeywell’s Moonyard Facility
- Real-time trajectory can be displayed and recorded
- Tracking accuracy within 1 inch in the xy plane and within 2 inches in the z direction
- Tracking data are passed to the robotic control system
UWB Relative Navigation – Vehicle Following

- The UWB TDOA tracking system at the following vehicle can track the leading vehicle in real time with a update rate of 1 hertz (Hz) by running the experimental code.
- It is anticipated that the update rate can be improved greater than 5 Hz with immigrants to the application code.
The system is being designed to provide the tracking capability inside the International Space Station (ISS) modules for various applications. One of applications is to locate and report the location where crew experienced possible high level of carbon-dioxide and felt upset.

In order to accurately locate those places in a multipath intensive environment like ISS modules, it requires a robust real-time location system (RTLS) which can provide the required accuracy and update rate. The designed system will be tested in the Wireless Habitat Testbed (WHT) which simulates the ISS module environment.
Why UWB?

- Immunity to interference from narrow band RF systems due to ultra-wide bandwidth
- Low impact on other RF systems due to extremely low power spectral densities
- Capable of precise tracking due to sub-nanosecond time resolution
- Robust performance in multipath environments
Time of Arrival (TOA)
(2D Illustration)
Linear TOA Equations (3D)

\[ Gp = h \]

\[ G = \begin{bmatrix} x_2 - x_1 & y_2 - y_1 & z_2 - z_1 \\ x_3 - x_1 & y_3 - y_1 & z_3 - z_1 \\ x_4 - x_1 & y_4 - y_1 & z_4 - z_1 \end{bmatrix}, \quad p = \begin{bmatrix} x \\ y \\ z \end{bmatrix}, \]

\[ h = \frac{1}{2} \begin{bmatrix} x_2^2 + y_2^2 + z_2^2 - c^2 t_2^2 - (x_1^2 + y_1^2 + z_1^2 - c^2 t_1^2) \\ x_3^2 + y_3^2 + z_3^2 - c^2 t_3^2 - (x_1^2 + y_1^2 + z_1^2 - c^2 t_1^2) \\ x_4^2 + y_4^2 + z_4^2 - c^2 t_4^2 - (x_1^2 + y_1^2 + z_1^2 - c^2 t_1^2) \end{bmatrix}. \]
In the presence of TOA measurement errors, the target radio location can be estimated using the standard least square solution

\[ \hat{p} = \arg \min (G\hat{p} - h)^T (G\hat{p} - h) \]

\[ = (G^T G)^{-1} G^T h. \]
P400 RCM (Ranging and Communication Module) from Time Domain Corporation

- RF transmissions from 3.1GHz to 5.3 GHz, with center at 4.3 GHz
- RF emissions compliant with FCC limits
- Each unit is a full transceiver
- High precision ranging with industry-leading update rate
- Typical range accuracy LOS: 3.5 cm
- Range Update Rate: 40 Hz to 3.5 Hz
- Max Distance (FCC Part 15 0dB Antennas, Free space): 88m, 125m, 177m, 250m, 354m (standard)

Currently UWB System Group owns two units
Within WHT, an rectangular cuboid with dimension 18 feet (L) x 6 feet (D) x 6 feet (H) is defined as the available tracking space where about 931 test points are set one foot apart. The standard deviation (STD) of TOA estimates 100 picoseconds is used in these simulations.
Simulation Results for Configuration “Twisted Rectangle”
Tracking Error Analysis for “Twisted Rectangle”
(average error = 0.2392 feet, STD = 0.1373 feet)
Simulation Results for Configuration “Slightly-Twisted Top Rectangle”
Tracking Error Analysis for “Slightly-Twisted Top Rectangle”
(average error = 0.9183 feet, STD = 0.6927 feet)
Simulation Results for Configuration “Twisted Rectangle” with 10 ps TOA_STD
Tracking Error Analysis for “Twisted Rectangle” with 10 ps TOA_STD
(average error = 0.0239 feet, STD = 0.0137 feet)
Summary and Future Work

A tracking performance evaluation has been conducted for the UWB TOA 3D Tracking System in the Wireless Habitat Testbed through simulation. The results show that two configurations of the tracking baseline are feasible to achieve the fine tracking accuracy.

Future work includes acquiring three more P400 RCM units to conduct 3D tracking tests with chosen baseline configuration and develop signal processing techniques to refine the TOA estimates so that the tracking accuracy can be further improved.