A Power Independent Detection Method for Ultra Wide Band (UWB) Impulse Radio Networks

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Abstract: We propose a novel detection method for non-coherent synchronization (signal acquisition) in multi-access UWB impulse radio (IR) networks. It is designed to solve the IUI (Inter-User Interference) that occurs in some ad-hoc networks where concurrent transmissions are allowed with heterogeneous power levels. In such scenarios, the conventional detection method, which is based on correlating the received IR signal with a Template Pulse Train (TPT), does not always perform well. Our proposal has similar complexity as the conventional method. We evaluate its performance with the Line Of Sight (LOS) office indoor channel model proposed by the IEEE P802.15.4a study group and find that the improvement is significant.

1 Introduction

We propose a novel detection method, called PID (Power Independent Detection) method, for non-coherent synchronization in multi-access Ultra Wide Band (UWB) Impulse Radio (IR) networks. To understand what we mean by detection method, let us define the following terminology. We consider the synchronization of one receiver to one sender (also called signal acquisition). We are interested in methods based on the correlation of the IR signal with a Template Pulse Train (TPT). Such methods involve two ingredients: (1) the detection, which correlates the received signal with a TPT and (2) the search algorithm, which shifts the TPT. We focus on detection. Our proposal aims at solving the extreme Inter-User Interference (IUI) case (near-far problem), when there are multiple interfering transmitters, asynchronous transmissions and heterogeneous power levels. This occurs for example in the presence of multiple interfering piconets, or in purely ad-hoc networks that allow concurrent transmissions, always at full power [4, 14]. In such scenarios the conventional detection method faces a certain failure. Our PID method solves the problem without any additional complexity overhead, e.g. for a digital receiver, it employs the same sampling frequency and number of operations as the conventional detection method. Unlike the conventional detection method, the PID method splits the correlation into elementary correlations, each one corresponds to one pulse in the TPT. Then, two threshold checks are performed. The first is to detect pulses whereas the second is to detect the signal based on the number of detected pulses. To evaluate the performance of the PID method, we propose a hybrid method combining analysis and simulation that is carried out according to the Line Of Sight (LOS) office indoor channel model proposed by the IEEE P802.15.4a study group [2]. The results presented in the end show a significant improvement compared to the conventional detection method.

The conventional detection method (detailed in 3.1) has been recently adopted in a large number of references, in combination with a variety of search algorithms; Some search algorithms are adequate for fine grained synchronization (e.g. serial [17]) or for coarse synchronization (e.g. "Look and Jump", Bit reversal [1, 11, 12], sequential block search [8] and n-scaled acquisition algorithms [18]). The conventional detection method suffers from the near-far problem with all these search algorithms. The PID method, is designed to replace it and solve the near-far problem with all the search algorithms. Further, the PID method can be generalized to all correlation-based synchronization methods (e.g. conventional one and others such as Differential Detector [10, 16, 21]) and it can be even used with a rake detector as proposed in [20], which do not operate well in case of near-far problem.

2 Model and Assumption:

An IR signal consists of trains of very short pulses to the order of a nanosecond or even a sub-nanosecond. In this paper we consider a Time Hopping (TH) physical layer proposed by Win-Scholtz [22]. TH is ensured using a pseudo-random code of length $L_c$. Such a physical layer can employ several modulation schemes such as BPSK (Binary Phase Shift Keying), PPM (Pulse Position Modulation), PAM (Pulse Amplitude Modulation); we do not have to specify a modulation scheme here since there is no data transmitted during the synchronization period and thus the signal we treat is not modulated. The transmitted signal of the $m^{th}$ user is:

$$s^{(m)} = A^{(m)} \sum_{j} \sum_{k=1} \tau_k \left( p \left( t - \left( c_k^{(m)} - 1 \right) T_c - (k - 1) T_f + j T_s - \tau_X^{(m)} \right) \right) \tag{1}$$

where $p(t)$ is the second derivative of the Gaussian pulse (Appendix1), $A^{(m)}$ is to indicate the signal amplitude, $T_c$ is the chip duration, $c_k^{(m)}$ is the $k^{th}$ element of the $m^{th}$ user code, i.e. the number of the chip that corresponds to the pulse position in the $k^{th}$ frame of a $m^{th}$ user sequence, $T_f = N_c \times T_c$ is the frame duration where $N_c$ is the number of chips in one frame, $T_s$ is the sequence duration, that is $T_s = T_f \times L_c$ and $\tau_X^{(m)}$ is the transmission start time. We assume that the pulse width and the chip duration are equal.

For our results, we consider the Saleh-Valenzuela (SV) channel model adopted in [2]. For simplicity, we express its impulse

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1All appendices cited in this paper belong to our technical report [6].
The response using the well-known tapped delay line expression:

\[ h(t) = \sum_{i=1}^{L} a_i \delta(t - t_i) \]  

(2)

where \( \delta(t) \) denotes the Dirac impulse, \( t_i \) the signal delay along the \( i^{th} \) path and \( a_i \) is a real propagation coefficient that includes the channel attenuation and the polarity of the signal along the \( i^{th} \) path. Then the received signal is given by:

\[ r(t) = \sum_{m=1}^{M} \sum_{l=1}^{L} a(m)_l \delta(m) \left( t - t_l^{(m)} \right) + n(t) \]  

(3)

where \( M \) is the number of users in the network and \( n(t) \) is the White Gaussian noise.

Assume that the receiver is interested in detecting the signal sent by the first user. Then, the objective of the synchronization methods that use either the PID or the conventional detection methods is to detect whether the first user is transmitting or not, and if he is transmitting, they find the arrival time of one sequence in the first user signal according to one of the multipath components, i.e., they find one value of \( \{ (T_X^{(1)} + jT_s + t_l^{(1)}) \}, l = 1, \ldots, L, j = 0, 1, \ldots \} \), let \( \tau_0 \) be the found value. Further it detects the sign of the corresponding \( a_l \).

3 Conventional Detection Method

3.1 Description

As it is explained in section 1, we consider synchronization methods that involve two ingredients: the detection and the search algorithm. With the conventional detection method, the received IR signal is correlated with a TPT, which is a replica of the sequence used by the first user and which is given by:

\[ s_{TPT}(t) = \sum_{k=1}^{L_c} p \left( t - (c_k^{(1)} - 1)T_c - (k - 1)T_f \right) \]  

(4)

The idea behind the correlation is to compare the TPT with the received impulse radio signal, which may or may not have the identical pattern of pulses as the TPT. Then a threshold check is performed on the output of the correlation (\( \beta \) in Eq. 5) to detect whether there is a match (an alignment) between the TPT and the received IR signal.

The role of the search algorithm is to shift the TPT with predefined time offsets so that the TPT is placed at various locations in time as compared to the received impulse radio signal until a match is obtained between them, i.e., they are aligned. The output of the cross-correlator is:

\[ \beta = \int_{\sum_{i=1}^{n} \text{Offset}, + T_s}^{\sum_{i=1}^{n} \text{Offset}} r(t) \times s_{TPT} \left( t - \sum_{i=1}^{n} \text{Offset} \right) dt \]  

(5)

where \( n \) is the current shift number and \( \text{Offset} \) is the time offset at the \( n^{th} \) shift of the TPT. Eq. 5 is known in the literature as a coherent integration, but in this paper we refer to it as a correlation between the TPT and the received IR signal (note that we do not assume that the receiver knows the channel). The receiver gets synchronized with the transmitter at the \( n^{th} \) offset if \( \sum_{i=1}^{n} \text{Offset} \), is equal to one value of the set \( \{ (T_X^{(1)} + jT_s + t_l^{(1)}) \}, l = 1, \ldots, L, j = 0, 1, \ldots \} \), and thus \( \tau_0 = \sum_{i=1}^{n} \text{Offset} \). Notice that, according to Eq. 4, Eq. 5 can be interpreted as \( L_c \) elementary correlations \( \{ (\alpha_k) \} \), \( k = 1, \ldots, L_c \), \( \alpha_k \) is the output of the elementary correlation \( k \) that corresponds to the \( k^{th} \) pulse in the TPT. We can write:

\[ \beta = \sum_{k=1}^{L_c} \alpha_k \]  

(6)

where:

\[ \alpha_k = \int_{(c_k^{(1)} - 1)T_c + (k - 1)T_f + \sum_{i=1}^{n} \text{Offset}, + T_s}^{(c_k^{(1)} - 1)T_c + (k - 1)T_f + \sum_{i=1}^{n} \text{Offset}} p \left( t - (c_k^{(1)} - 1)T_c \right. \]

\[ - (k - 1)T_f - \sum_{i=1}^{n} \text{Offset}) \times r(t)dt \]  

(7)

These \( L_c \) elementary correlations correspond to the \( L_c \) correlations of the TPT pulses and their corresponding intervals of the IR signal. In Fig. 1, the \( L_c \) elementary correlations are presented by the blocks indexed from 1 to \( L_c \). \( \beta \) is the input of the decision block, which in turn performs a threshold check. Hence, a match between the TPT and the IR signal is declared if the absolute value of \( \beta \) exceeds certain threshold \( \gamma \). Note that a (-1) output of the decision block means that a match is declared but the signal is inverted due to reflection, i.e., the corresponding \( a_l \) is negative (see previous section).

3.2 Example Showing the Problem with the Conventional Detection Method

To show the inefficiency of the conventional detection method, we present one scenario that is based on the measurement made by M. Win and R. Scholtz in [23] for an indoor environment. Consider a source (user 1) that is 10 m from the receiver. The measurement in [23] gives that the amplitude of the strongest source pulse seen by the receiver is in the order of 0.03V. Assume now that there is an interferer (user 2) that is 1m from the receiver. The measured amplitude of the interfering pulse is of 1V, 33 times higher than the source pulse. Refer by \( A_r^{(1)} \) (\( A_r^{(2)} \) respectively) to the source (interferer respectively) signal amplitude at the receiver, we have \( A_r^{(2)} \approx 33A_r^{(1)} \). Let \( \alpha_0^{(1)} \) (\( \alpha_0^{(2)} \) respectively) be the output of the correlation between one source (interferer respectively) pulse and one TPT pulse when they are aligned, we can write:

\[ \alpha_0^{(1)} = A_r^{(1)} \int_{0}^{T_c} p^2(t)dt = \frac{A_r^{(1)}T_c}{33} \int_{0}^{T_c} p^2(t)dt \approx \frac{\alpha_0^{(2)}}{33} \]  

(8)
The absolute value of $\alpha_k$ is larger than $\theta$, then a pulse is detected and the output of the elementary decision block $k$ will be 1 or 0 depending on the sign of $\alpha_k$ (-1 means the detected pulse has negative polarity). Otherwise it will be 0. Let $\chi$ be the sum of the $L_c$ Elementary Decision block outputs, we have:

$$\chi = \sum_{k=1}^{L_c} (1_{\{\alpha_k \geq \theta\}} - 1_{\{\alpha_k \leq -\theta\}}) \in \{-L_c, \ldots, 0, \ldots, L_c\} \quad (9)$$

If the absolute value of $\chi$ is larger than the main threshold $mTh$, the output of the main decision block will be 1 or -1 (detected path is with negative polarity) and thus a match will be declared between the IR signal and the TPT. In the opposite case the output of the main decision block will be 0. $mTh$ should be a natural number less than $L_c$.

It is intuitively clear that this new method should solve the problem described in section 3.2; it is designed for an environment without power control since it is sensitive to the existence of a pulse not to its power (assuming it has enough energy to be detected). So we call our proposal "Power-Independent Detection".

5 Performance Evaluation Method

We evaluate the performance of PID and compare it to the conventional detection method.

5.1 How to Evaluate the Performance

For a meaningful performance evaluation of the conventional detection and the PID methods, we imbedded them in a complete synchronization method, which consists of an identification phase, followed by a verification phase. Each phase uses the two aforementioned ingredients of detection and search algorithm iteratively. For the latter, we adopted serial search. This is because we aim to evaluate the performance of the PID method independently of the impact of optimizations that use coarse synchronization.

The Complete Synchronization Method: When the complete synchronization method uses PID, we call it "PID synchronization method"; when it uses conventional detection, we call it "conventional synchronization method".

Let $N$ be the number of the search bins (Appendix [6]); let "true sequence" be the sequence to be detected in the received IR signal; it has the same pattern as the TPT. The largest $\chi_{\text{max}}$, is memorized, as well as its corresponding search bin. Then $\chi_{\text{max}}$ is compared to a first mean threshold, $mTh_1$. If the absolute value of $\chi_{\text{max}}$ is strictly above $mTh_1$, the bin that corresponds to $\chi_{\text{max}}$ is considered as a signal bin, $SB$, and we move to the second phase. Otherwise, the procedure of the first phase starts anew.

In the second phase we aim to verify the detection of the first phase. It consists of $A$ iterations, in each one the procedure is
the same as in the first phase but on a predefined neighborhood of $SB_i$, including $SB_i$ instead of the whole $N$ bins, and with a second mean threshold, $m$Th$2$, that is larger than $m$Th$1$. If at least $B$ threshold checks among $A$ succeed, the detection is confirmed, otherwise the detection of the first phase is cancelled and the procedure of the first phase starts anew.

The conventional synchronization method is similar to the PID synchronization method with the difference that it does not perform a threshold check on the elementary correlation outputs.

**Performance Metrics:** We measure the performance of each procedure by the following metrics, applied to the synchronization method: (1) the complement of the probability of Good Detection ($P_{GD} = 1 - P_{GD}$) in the presence of the true sequence in the received IR signal (2) the probability of false alarm, $P_{FA0}$, in the absence of the true sequence in the received IR signal and (3) the total error defined as $E_t = P_{GD} + P_{FA0}$. Note that the probability of false alarm in the presence of the true sequence is included in $P_{GD}$ and it does not give additional information about the total error, hence, for brevity, we do not consider it here as a metric.

### 5.2 Computation of Metric Using Hybrid Method: Analysis + Simulation

#### 5.2.1 Analysis:

The goal of the analysis is to express the metrics as functions of other probabilities that we obtain by simulation. The probabilities are as follows: During the first phase we have $P_1$, the probability of good detection when the received IR signal contains the true sequence, and $P_2$, the probability of a bad detection when the received IR signal does not contain the true sequence. During the second phase we define $P_3$ as the probability that one threshold check succeeds, given that the first phase has resulted in a good detection in the presence of the true sequence and $P_4$ as the Probability that one threshold check succeeds, given that the first phase has resulted in a bad detection in the absence of the true sequence.

The Analysis presented in Appendix [6] gives:

$$P_{GD} = 1 - P_1 \sum_{i=B}^{A} \binom{A}{i} P_3^{i} (1 - P_3)^{(A-i)} \quad (10)$$

$$P_{FA0} = P_2 \sum_{i=B}^{A} \binom{A}{i} P_4^{i} (1 - P_4)^{(A-i)} \quad (11)$$

#### 5.2.2 Simulation:

In order to compute the metrics, we ran a campaign of simulations to estimate the probabilities $P_i$, $i = 1, \ldots, 4$. The simulations were carried out using matlab. We tried to make the simulated scenario as realistic as possible by choosing a real multipath fading channel model and by adjusting all simulation parameters, e.g., the bit energy to noise spectral density ratio $E_0/N_0$ (one bit corresponds to one pulse), the physical layer parameters, the transmission power levels, the number of users.

**Channel Model:** The simulations were carried out according to the Line of Site (LOS) indoor office channel model described in [2] for a communication range from 3 m to 28 m. This model is the fruit of a campaign of industrial and academic contributions. The NLOS (Non LOS) is not considered since its parameter values are not available yet in [2].

Although the measurements made for this model were using an UWB IR signal, the model is generalized to be used by any carrier modulation system. Thus, the phase of a multipath component is considered as uniformly distributed over $[0,2\pi]$ which is meaningless in an UWB IR baseband transmission. We solve this problem by relaxing this hypothesis and replacing it by the one adopted in [3], which is appropriate for IR baseband transmission. Then, the phase of a multipath component will be $0/\pi$ with an equal probability for representing pulse inversion due to the reflection from different surfaces.

For simplicity, we assume that the distribution of the small scale fading is Rayleigh instead of Nakagami since the mean value in dB of the “m” parameter of the Nakagami distribution in the adopted model is very close to zero, which corresponds to the particular case of the Rayleigh distribution.

**Simulation Parameters:** We consider that all users are sending non-modulated IR signals, an assumption that does not affect our results since the interferer signals are already random with respect to the receiver and using data modulation will add one more random variable with zero mean. We have $T_v = 0.2\text{ns}$, $N_v$ is set to 200 chips that corresponds to 40 ns, which is sufficient to minimize the inter-symbol interference due the multipath delay spread in the LOS indoor office environment [7, 13], in particular we consider a guard time of 100 chips. The sampling frequency is 50 GHz, much larger than the Nyquist sampling frequency, to simulate an analog receiver since the impact of the interferer signals is already random with respect to them as users, the one that is transmitting the true sequence is the farthest. Such a communication range is typical for an indoor office environment and the adopted channel model of [2] is still valid since it is based on measurements that cover a range from 3 m to 28 m.

In all simulated scenarios, $E_0/N_0$ is computed with respect to the source signal power.
6 Performance Evaluation Results

6.1 Performance Evaluation Results of the PID Synchronization Method

The probabilities $P_i$, $i = 1, \ldots, 4$, are obtained by simulation. $P_1$ and $P_2$ are computed by averaging the results of 200 independent runs for each simulated scenario. A different independent noise realization is computed per run and, within the same run, a different channel realization is computed per user.

To compute $P_3$ and $P_4$, the stationarity of the channel during the synchronization should be taken into account. Thus, the computation of $P_3$ and $P_4$ is different and more complicated. We proceed as follows: for each run of the 200 runs above, if a detection is declared, 9 other runs are done with the same channel realization for each user but with different noise realization. Then, for a given scenario, if all the 200 runs above result in a detection declaration, we will have 9 additional runs for each run and thus 1800 runs for this scenario.

We ran simulations for $E_0/N_0$ values between 0 dB and 20 dB, $L_c$ values between 8 and 30, and number of users between 5 and 20 users. In the extreme scenarios with low $E_0/N_0$ (< 10 dB), short $L_c$ (< 16) and large number of users (20 users) the performance was not so good due to a huge amount of interference and noise. But, starting from $E_0/N_0 = 10$ dB and $L_c = 16$, the performance is acceptable and the results seem to be similar. For lack of space, we show only one scenario in order to explain the behavior of the PID synchronization method and to show the optimal working point.

Fig. 3 (a), (b) and (c) shows the metrics $P_{GD}$, $P_{FA0}$ and $E_t$ (see the legend for details). We tried to draw results for a range of 9 – 19 for mTh1 and mTh2, but sometimes the values were too small (less than 10e-25) and matlab was not able to draw them. For Fig. 3 (a), the interpretation is as follows: first notice that $P_{GD}$ is decreasing with $P_3$. For a given mTh1, $P_3$ is a decreasing function of mTh2, whereas $P_1$ is independent of mTh2. Consequently, $P_{GD}$ is an increasing function of mTh2. In contrast, for a given mTh2, $P_1$ is a decreasing function of mTh1 but $P_3$ increases with mTh1 since it is a conditional probability that $\chi_{max}$ in one iteration of the second phase is above mTh2 given that $\chi_{max}$ in the first phase is above mTh1 and the difference between mTh1 and mTh2 decreases when mTh1 increases. Therefore, given mTh2, it is not evident how $P_{GD}$ varies according to mTh1 since $P_1$ and $P_3$ vary in opposite directions. Moreover the values of A and B influence the impact of the variation of $P_3$. For mTh2 = 18, $P_{GD}$ increases with mTh1 when mTh1 goes from 12 to 17, but it decreases when mTh1 passes from 17 to 18. Fig. 3 (b) shows the probability $P_{FA0}$. To understand the trends of the curves, a similar interpretation can be made as above. For instance, for a given mTh1, $P_2$ is independent of mTh2 and $P_4$ is a decreasing function of mTh2. Thus, $P_{FA0}$ decreases with mTh2 for a fixed mTh1. In contrast, for a fixed mTh2, $P_2$ is decreasing with mTh1 whereas $P_3$ is increasing.

Fig. 3 (c) shows $E_t$. The optimal working point for this scenario is for (mTh1:mTh2) = (10:12) where $E_t$ is minimized. On the left hand of the optimal working point, $P_{FA0}$ is dominant and the curves imitate those of $P_{FA0}$ in Fig. 3 (b). In contrast, $P_{GD}$ becomes dominant on the right hand of the optimal working point and the curves at this side are similar to those of $P_{GD}$ in Fig. 3 (a).

In conclusion, using the PID synchronization method, an optimal working point can be obtained by minimizing $E_t$. For this specific example, the optimal working point is $mTh1 = 10$, $mTh2 = 12$.

6.2 Comparison between the PID and the Conventional Synchronization Methods:

To show the performance of the conventional complete method, we computed a lower bound of its $P_{GD}$. According to Eq. 10, a lower bound of $P_{GD}$ is $1 - P_1$, which is independent of the second phase. Further, a lower bound of $1 - P_1$ can be simply obtained by relaxing the mTh1 threshold check in the first phase (which returns as if we set mTh1 to zero). Then, a good detection is obtained if $\beta_{max}$ ($\chi_{max}$ with the PID synchronization method) corresponds to a signal bin without any constraint on its value.

For the conventional complete method, the lower bound of $P_1$ for a given scenario is obtained by averaging the results of 30 independent runs for this scenario. Fig. 4 (a) shows two curves as functions of $E_0/N_0$ in dB. The first curve (according to the order in the legend) corresponds to the PID synchronization method. It represents $P_{GD}$ values at the optimal working points and that are obtained in the same way as in the section above. Corresponding values of $E_t$ are shown in Fig. 4 (b). The second curve
Figure 3: Performance of PID for various values of the two thresholds mTh1 and mTh2 defined in Section 5.1; mTh2 is on the x-axis, mTh1 is the x-value of the leftmost point on each curve. The y-axis shows: (a) $P_{GD}(1-P_{GD})$ (the complement of the probability of Good Detection), (b) $P_{FA0}$ (the probability of False Alarm) and (c) $E_t = P_{GD} + P_{FA0}$ (the total error). $E_0/N_0 = 15$ dB, $L_c = 20$, 10 users, $A = 10$ and $B = 7$.

| References |
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