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***KERNEL AND MULTI-CLASS CLASSIFIERS FOR MULTI-FLOOR WLAN
LOCALISATION***

MOHD AMIRUDDIN BIN ABD RAHMAN

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LOCALISATION**

By

MOHD AMIRUDDIN BIN ABD RAHMAN

**Thesis Submitted to the School of Graduate Studies, Universiti Putra
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the Degree of Doctor of Philosophy**

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By

MOHD AMIRUDDIN BIN ABD RAHMAN

June 2016

Chair: Associate Professor Zulkifly Abbas, PhD

Faculty: Science

Indoor localisation techniques in multi-floor environments are emerging for location based service applications. Developing an accurate location determination and time-efficient technique is crucial for online location estimation of the multi-floor localisation system. The localisation accuracy and computational complexity of the localisation system mainly relies on the performance of the algorithms embedded with the system. Unfortunately, existing algorithms are either time-consuming or inaccurate for simultaneous determination of floor and horizontal locations in multi-floor environment. This thesis proposes an improved multi-floor localisation technique by integrating three important elements of the system; radio map fingerprint database optimisation, floor or vertical localisation, and horizontal localisation. The main focus of this work is to extend the kernel density approach and implement multi-class machine learning classifiers to improve the localisation accuracy and processing time of the each and overall elements of the proposed technique.

For fingerprint database optimisation, novel access point (AP) selection algorithms which are based on variant AP selection are investigated to improve computational accuracy compared to existing AP selection algorithms such as Max-Mean and InfoGain. The variant AP selection is further improved by grouping AP based on signal distribution. In this work, two AP selection algorithms are proposed which are Max Kernel and Kernel Logistic Discriminant that implement the knowledge of kernel density estimate and logistic regression machine learning classification.

For floor localisation, the strategy is based on developing the algorithm to determine the floor by utilising fingerprint clustering technique. The clustering method is based on simple signal strength clustering which sorts the signals of APs in each fingerprint according to the strongest value. Two new floor localisation algorithms namely Averaged Kernel Floor (AKF) and Kernel Logistic

Floor (KLF) are studied. The former is based on modification of univariate kernel algorithm which is proposed for single-floor localisation, while the latter applies the theory kernel logistic regression which is similar to AP selection approach but for classification purpose.

For horizontal localisation, different algorithm based on multi-class k -nearest neighbour (k NN) classifiers with optimisation parameter is presented. Unlike the classical k NN algorithm which is a regression type algorithm, the proposed localisation algorithms utilise machine learning classification for both linear and kernel types. The multi-class classification strategy is used to ensure quick estimation of the multi-class k NN algorithms.

The proposed algorithms are compared and analysed with existing algorithms to confirm reliability and robustness. Additionally, the algorithms are evaluated using six multi-floor and single-floor datasets to validate the proposed algorithms. In database optimisation, the proposed AP selection technique using Max Kernel could reduce as high as 77.8% APs compared to existing approaches while retaining similar accuracy as localisation algorithm utilising all APs in the database. In floor localisation, the proposed KLF algorithm at one time could demonstrate 93.4% correct determination of floor level based on the measured dataset. In horizontal localisation, the multi-class k NN classifier algorithm could improve 19.3% of accuracy within fingerprint spacing of 2 meters compared to existing algorithms.

All of the algorithms are later combined to provide device location estimation for multi-floor environment. Improvement of 43.5% of within 2 meters location accuracy and reduction of 15.2 times computational time are seen as compared to existing multi-floor localisation techniques by Gansemer and Marques. The improved accuracy is due to better performance of proposed floor and horizontal localisation algorithm while the computational time is reduced due to introduction of AP selection algorithm.

Abstrak tesis yang dikemukakan kepada Senat Universiti Putra Malaysia dan University of Sheffield sebagai memenuhi keperluan untuk ijazah Doktor Falsafah

KERNEL DAN KLASIFIKASI KELAS PELBAGAI UNTUK LOKALISASI BANGUNAN BERTINGKAT WLAN

Oleh

MOHD AMIRUDDIN BIN ABD RAHMAN

Jun 2016

Pengerusi: Profesor Madya Zulkifly Abbas, PhD

Fakulti: Sains

Teknik lokalisasi dalam bangunan untuk bangunan bertingkat sedang memunculkan untuk aplikasi berdasarkan servis lokasi. Membangunkan sistem yang tepat dan cekap masa penting untuk anggaran lokasi semasa dalam bangunan bertingkat. Ketepatan dan kecekapan masa system bergantung terutamanya kepada prestasi algoritma yang terbenam dalam sistem. Namun, algoritma sedia ada adalah kurang cekap atau kurang tepat untuk dibangunkan dalam bangunan bertingkat. Tesis ini mencadangkan system lokalisasi bertingkat yang di tambah baik. Tiga elemen penting sistem iaitu pengoptimuman pangkalan data, lokalisasi lantai atau menegak, dan lokalisasi mendatar disepadukan dalam teknik lokalisasi bertingkat. Fokus utama kerja ini ialah untuk menambah baik ketepatan dan kecekapan pengiraan algoritma dengan mengambil kira setiap elemen tersebut.

Untuk pengoptimuman pangkalan data, teknik pemilihan titik akses (TA) yang baharu berdasarkan pemilihan TA berbeza dikaji untuk menambah baik ketepatan pengiraan berbanding teknik pemilihan TA yang lepas. Pemilihan TA berbeza seterusnya ditambah baik dengan mengumpul TA berdasarkan ciri signal. Berdasarkan aspek ini, dua algoritma pemilihan TA dicadangkan iaitu algoritma Max Kernel dan Kernel Logistic Discriminant yang menggunakan ilmu anggaran ketumpatan kernel dan klasifikasi pembelajaran mesin regresi logistik.

Untuk lokalisasi lantai, strategi adalah berdasarkan menggabungkan teknik pengklusteran fingerprint dengan algoritma lokalisasi lantai. Kaedah pengklusteran adalah berdasarkan pengklusteran kekuatan signal mudah dengan menyusun signal TA di setiap fingerprint berdasarkan nilai paling kuat. Dua algoritma lokalisasi lantai dinamakan algoritma Averaged Kernel Floor dan Kernel Logistic Floor dikaji. Algoritma pertama adalah berdasarkan pengubahsuaian algoritma kernel univariate yang digunakan untuk lokalisasi

satu aras. Algoritma kedua menggunakan teori kernel regresi logistic yang sama dengan teknik pemilihan TA tetapi untuk tujuan klasifikasi.

Untuk lokalisasi mendatar, algoritma lokalisasi berbeza berdasarkan algoritma klasifikasi kelas pelbagai k -nearest neighbour (k NN) dengan parameter pengoptimum dicadangkan. Tidak sama seperti algoritma k NN klasik yang merupakan algoritma jenis regresi, algoritma lokalisasi yang dicadangkan juga berdasarkan pengklasifikasi pembelajaran mesin. Algoritma tersebut dicadangkan dalam dua versi iaitu linear dan kernel. Strategi pelbagai-kelas untuk klasifikasi digunakan untuk memastikan anggaran pantas algoritma k NN pelbagai-kelas.

Kesemua algoritma yang dibangunkan dibandingkan secara sendiri dan dianalisa dengan algoritma terdahulu untuk mengesahkan kejitian dan kemapanan. Di samping itu, penilaian algoritma dibuat dengan pelbagai pangkalan data bertingkat dan satu aras untuk memastikan kebolehgunapakaian algoritma yang dicadangkan. Dalam pengoptimuman pangkalan data, algoritma pemilihan TA yang dicadangkan boleh mencapai sehingga 91.3% ketepatan di antara lokasi 2 meter dan pada masa yang sama menurunkan 17.7% kerumitan pengiraan. Dalam lokalisasi lantai, algoritma lantai yang dicadangkan menunjukkan sehingga 96.8% ketepatan lantai. Dalam lokalisasi mendatar, algoritma yang dibangunkan mencapai sehingga 93.7% ketepatan di antara lokasi 2 meter.

Algoritma tersebut kemudian digabungkan untuk menganggarkan lokasi peranti untuk bangunan bertingkat. Keputusan purata 73.6% ketepatan di antara lokasi 2 meter dan 93.4% ketepatan lantai menunjukkan peningkatan berbanding teknik terdahulu oleh Gansemer dan Marques. Penambahbaikan kejitian disebabkan oleh prestasi algoritma lokalisasi lantai dan mendatar yang lebih baik manakala pengurangan kerumitan pengiraan disebabkan oleh pengenalan algoritma pemilihan TA.

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Zulkifly Bin Abbas, PhD

Associate Professor
Faculty of Science
Universiti Putra Malaysia
(Chairman)

Jie Zhang, PhD

Professor
Department of Electronic and Electrical Engineering
University of Sheffield
(Member)

Alyani Binti Ismail, PhD

Associate Professor
Faculty of Engineering
Universiti Putra Malaysia
(Member)

Xiaoli Chu, PhD

Lecturer
Department of Electronic and Electrical Engineering
University of Sheffield
(Member)

BUJANG KIM HUAT, PhD

Professor and Dean
School of Graduate Studies
Universiti Putra Malaysia

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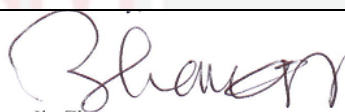
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Name of Chairman
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Committee:



Signature: _____

Name of Member of
Supervisory
Committee:

PROF DR JIE ZHANG

Signature: _____

Name of Member of
Supervisory
Committee:



Signature: _____

Name of Member of
Supervisory
Committee:

DR XIAOLI CHU

TABLE OF CONTENTS

	Page
ABSTRACT	i
ABSTRAK	iii
ACKNOWLEDGEMENTS	v
APPROVAL	vi
DECLARATION	viii
LIST OF TABLES	xv
LIST OF FIGURES	xviii
LIST OF ABBREVIATIONS	xxvi
LIST OF SYMBOLS	xxviii
 CHAPTER	
 1 INTRODUCTION	 1
1.1 Overview	1
1.2 WLAN Indoor Localisation	2
1.3 Multi-floor Localisation	3
1.4 Kernel and Multi-Class Classifier Approach for Multi-Floor Localisation	4
1.5 Problem Statement	5
1.6 Objective of the Research	6
1.7 Organisation of the Thesis	7
 2 LITERATURE REVIEW	 9
2.1 Introduction	9
2.2 Multi-floor WLAN Localisation	9
2.3 Preparation of Datasets for Multi-floor Localisation	11
2.4 Multi-floor Localisation Fingerprint Database	11
2.4.1 AP Selection Mechanism	12
2.5 Fingerprint Versus AP-based Technique	13
2.6 Multi-floor WLAN Fingerprint Localisation	14
2.6.1 Single-stage Multi-floor Localisation Algorithm	14
2.6.2 Two-stage Multi-floor Localisation Algorithm	14
2.7 System Performance of Existing WLAN Fingerprint Multi-floor Indoor Localisation	16
2.7.1 Trilateration	18
2.7.2 Similarity Function	19
2.7.3 Machine Learning Classification	19
2.7.4 Artificial Neural Network	20
2.7.5 Path Loss Model	21

2.8	Summary of WLAN Multi-floor Localisation	22
3	KERNEL AND MULTI-CLASS CLASSIFIER: THEORY AND ALGORITHMS	23
3.1	Introduction	23
3.2	Basics of WLAN Fingerprinting Localisation System	23
3.3	Classical WLAN Fingerprint Localisation Algorithms	26
3.3.1	k -Nearest Neighbour	26
3.3.2	Probabilistic Method	27
3.4	Main Processing Blocks of Proposed WLAN Multi-floor Localisation System	29
3.5	Kernel Density Estimate (KDE) as a Tool for AP Selection and Floor	30
3.5.1	Characterising AP Signals Based on KDE of Signal Distribution for AP	32
3.6	Machine Learning Classification As a Tool For AP Selection, Floor and Horizontal Localisation Algorithm	34
3.6.1	Kernel Trick for Classifiers	36
3.6.2	Logistic Regression and k -Nearest Neighbour Classifiers for Multi-Floor Localisation	36
3.6.3	Logistic Regression Classifier	37
3.6.4	k -Nearest Neighbour Classifier	38
3.7	Radio Map Fingerprint Database Optimisation By Max Kernel and Kernel Logistic Discriminant Pairwise AP Selection	38
3.7.1	Variant AP Selection Technique	39
3.7.2	Max Kernel	40
3.7.3	Kernel Logistic Pairwise Discriminant (KLPD)	41
3.8	Averaged Kernel and Kernel Logistic Floor Localisation Algorithms	44
3.8.1	Floor Signal Strength Clustering	44
3.8.2	Averaged Kernel Floor Algorithm	46
3.8.3	Kernel Logistic Floor Algorithm	47
3.9	Horizontal Localisation Algorithm	49
3.9.1	Multi-class k -Nearest Neighbour Classifiers as Horizontal Localisation Algorithm	49
3.9.2	Optimisation of the Multi-Class k NN Classifier	51
3.9.3	Kernel Multi-class k NN Classifier	52
3.10	Summary	52
4	MEASUREMENT AND METHODS	54
4.1	Introduction	54

4.2	Measurement and Computation Tools	54
4.3	Measurement Environments and Locations	56
4.4	Radio Map Database and The Measured Signal Statistics	59
4.5	Additional Datasets	60
4.5.1	CRAWDAD	60
4.5.2	Antwerp	61
4.5.3	Dublin	62
4.6	Statistics of Radio Map Database of Several UPM's and Bell Lab's Buildings, and CRAWDAD	64
4.7	Online Test Samples	66
4.8	Extraction of the Path Loss Parameters of Measured Signal of Radio Map Database	66
4.8.1	CRAWDAD	67
4.9	Performance Metrics of Multi-Floor Localisation System	71
4.9.1	Accuracy	72
4.9.2	Precision	73
4.9.3	Computational Complexity	74
4.10	Choosing Value of k in k NN Localisation Algorithm	74
4.11	Summary	75
5	RESULTS AND DISCUSSION I: PERFORMANCE OF MAX KERNEL AND KERNEL LOGISTIC PAIRWISE DISCRIMINANT AP SELECTION ALGORITHMS	76
5.1	Introduction	76
5.2	Accuracy of Localisation of Different Number of Selected APs By Pairing Max Kernel and KLPD with Univariate Kernel, Multivariate Kernel and NN Localisation Algorithms	76
5.2.1	Single-floor Performance Using Univariate Kernel Algorithm	77
5.2.2	Multi-floor Performance Using Univariate Kernel Algorithm	81
5.2.3	Single-floor Performance Using Multivariate Kernel Algorithm	83
5.2.4	Multi-floor Performance Using Multivariate Kernel Algorithm	86
5.2.5	Single-floor Performance Using k NN algorithm	89
5.2.6	Multi-floor Performance Using k NN algorithm	91

5.3	Effect of Reducing the Number of Fingerprint Measurement Samples, T to Max Kernel and KLPD AP Selection Paired with Univariate Kernel, Multivariate Kernel, and kNN Localisation Algorithm	94
5.4	APs Reduction By Different AP selection Techniques on Univariate Kernel, Multivariate Kernel, and kNN Localisation Algorithms	99
5.4.1	Single-floor Performance Using Univariate Kernel Algorithm	101
5.4.2	Multi-floor Performance Using Univariate Kernel Algorithm	102
5.4.3	Single-floor Performance Using Multivariate Kernel Algorithm	104
5.4.4	Multi-floor Performance Using Multivariate Kernel Algorithm	106
5.4.5	Single-floor Performance Using kNN algorithm	106
5.4.6	Multi-floor Performance Using kNN algorithm	107
5.5	Comparison of Computation Time of Using Different AP Selection Techniques	108
5.6	Summary	110
6	RESULTS AND DISCUSSION II: PERFORMANCE OF AVERAGE KERNEL FLOOR AND KERNEL LOGISTIC FLOOR LOCALISATION ALGORITHMS	111
6.1	Introduction	111
6.2	Number of Clusters Per Dataset of The AKF and KLF Algorithms	111
6.3	Accuracy of Floor Estimation Using AKF and KLF Algorithms	112
6.4	Comparison of Floor Localisation Algorithms with Original Findings	114
6.5	Per Floor Analysis of AKF and KLF Localisation Algorithms	115
6.6	Computational Complexity of AKF and KLF Localisation Algorithms	117
6.7	Effect of Number of Fingerprint Measurement Samples, T on AKF and KLF Localisation Algorithms	118
6.8	Combining The Proposed Max Kernel AP selection with AKF and KLF Floor Localisation Algorithms	119
6.9	Summary	121

7	RESULTS AND DISCUSSION III: PERFORMANCE OF NORMAL AND KERNEL MULTI-CLASS KNN CLASSIFIER HORIZONTAL LOCALISATION ALGORITHMS	122
7.1	Introduction	122
7.2	Effect of Number of Estimated locations k and Optimisation Parameter ϖ of the Multi-class k NN Classifier	122
7.3	Effect of σ in Kernel k NN Classifier	123
7.4	Precision and Accuracy of Multi-Class k NN Classifier and Comparison with Other Horizontal Localisation Algorithms	125
7.5	Effect on Number of Fingerprint Measurement Samples, T to Multi-Class k NN Classifiers	130
7.6	Effect of the Number of APs Per Fingerprint on the Multi-Class k NN Classifiers	132
7.7	Combining the Proposed Max Kernel AP Selection with Multi-Class k NN Classifier Algorithm	135
7.8	Summary	136
8	RESULTS AND DISCUSSION IV: MULTI- FLOOR LOCALISATION ALGORITHM	137
8.1	Introduction	137
8.2	Precision and Accuracy of Proposed Multi-Floor Localisation Algorithm	137
8.3	Computational Complexity of the Proposed Multi-Floor Localisation Algorithm	139
8.4	Summary	140
9	CONCLUSION AND FUTURE WORKS	141
9.1	Summary of the Thesis	141
9.2	Contributions	142
9.3	Recommendations for Future Works	144
	REFERENCES	146
	APPENDICES	153
	BIODATA OF STUDENT	174
	LIST OF PUBLICATIONS	175

LIST OF TABLES

Table	Page
1.1	5
2.1	15
2.2	17
3.1	53
4.1	54
4.2	56
4.3	58
4.4	65
4.5	66
4.6	69
5.1	95
5.2	100
5.3	100
5.4	102
5.5	104

5.6	Number of APs required achieving upper 95% confidence limit and percentage of AP reduction by different AP selection algorithm paired with multivariate kernel algorithm in single-floor environments	105
5.7	Number of APs required achieving upper 95% confidence limit and percentage of AP reduction by different AP selection algorithm paired with multivariate kernel algorithm in multi-floor environments	106
5.8	Number of APs required achieving upper 95% confidence limit and percentage of AP reduction by different AP selection algorithm paired with <i>k</i> NN algorithm in single-floor environments	107
5.9	Number of APs required achieving upper 95% confidence limit and percentage of AP reduction by different AP selection algorithm paired with <i>k</i> NN algorithm in multi-floor environments	107
5.10	Computation times of univariate kernel, multivariate kernel, and <i>k</i> NN using different AP selection technique in Building A, B, and C for single-floor dataset	110
5.11	Computation times of univariate kernel, multivariate kernel, and <i>k</i> NN using different AP selection technique in Building A, B, and C for single-floor dataset	110
6.1	Comparison of number of clusters processed by signal strength clustering algorithm and number of original fingerprints in each tested building	112
6.2	Numerical results of cumulative density function plot of Figure 6.1	114
6.3	Tested floor localization algorithms with reported results	114
6.4	Floor localisation algorithms with this work database setup and reported result	115
6.5	Variance of estimation accuracy of each algorithm in every building	117
7.1	Error measures of different horizontal positioning algorithm in Building A, B, C, CRAWDAD, Antwerp, and Dublin	128
8.1	Error measure of Gansemer, Marques, and proposed combined Max Kernel, AKF, and MkNN algorithms	138
C1.1	Comparison of different AP selection techniques	166
D1.1	Comparison of floor localisation algorithm techniques	168

E1.1	Value of optimised ϖ for linear and kernel k NN classifier algorithms in Building A, B, and C at different number of training samples	169
E1.2	Value of optimised ϖ for linear and kernel k NN classifier algorithms in Building A, B, and C, CRAWDAD, Antwerp, and Dublin at different number of selected APs	170
F2.1	Number of selected APs for proposed multi-floor localisation algorithm in different buildings	173
F2.2	Majority rules for Marques' multi-floor localisation algorithm in different buildings	173
F2.3	Parameters of Gansemer's multi-floor localisation algorithm in all tested buildings	173

LIST OF FIGURES

Figure		Page
1.1	WLAN indoor localisation in single-floor and multi-floor settings	3
2.1	Graphical summary of existing works in multi-floor indoor localisation system	10
2.2	AP Selection mechanism with subset of three APs	13
2.3	Pairwise RSS of AP1 and AP2 in three different classes (locations) for classification based on machine learning	20
2.4	ANN scheme for multi-floor localisation where the inputs consists of RSS of multiple APs and the outputs is the x, y, and z location coordinate	21
3.1	Basic architecture of WLAN fingerprint indoor localisation system	24
3.2	Signal measurement process by measuring the signal strength of multiple APs at allocated locations	25
3.3	Entry of a radio map fingerprint database of a fifth floor level in a building	25
3.4	Univariate kernel versus multivariate kernel for two APs case	28
3.5	Architecture of proposed WLAN fingerprint multi-floor localisation system	30
3.6	Example of multi-floor radio map database layout	30
3.7	Comparison of (a) kernel density estimate, (b) histogram, and (c) Gaussian density estimate	32
3.8	Kernel density estimate of (a) Strong AP and (b) Weak AP where the missing signal is determined as -100 dBm	33
3.9	Top figure shows projection of fingerprint dataset into feature space for classification. The AP pair data is found at three different locations (classes) and OVA, OVO, and multiclass scheme are compared	35
3.10	Classical versus Variant AP Selection Technique for four selected APs	39
3.11	Example of kernel density estimate of six APs at one fingerprint location	41
3.12	Flow chart of Max Kernel AP selection algorithm	42
3.13	Flowchart of Kernel Logistic Pairwise Discriminant AP selection algorithm	43

3.14	Floor signal strength clustering of five fingerprint entries which groups as three clusters	45
3.15	Flow chart of the proposed floor signal strength clustering	45
3.16	Flow chart of Averaged Kernel Floor algorithm	46
3.17	OVO scheme of each round of online signal vector $\mathbf{r}_o^v$ in KLF algorithm	48
3.18	Flow chart of the proposed Kernel Logistic Floor algorithm	48
3.19	Comparison of (a) classical k NN algorithm and (b) k NN classifier for 3 AP case	50
3.20	Example of optimisation parameter used in k NN classification with $\varpi = 3$ to calculate averaged signal distance S using example in the bottom most figure in Figure 4.12(b)	51
4.1	The interface of the Android Airplace Logger application which shows (a) the main screen where the user can record the fingerprint data, and (b) the configuration screen where the user can set the fingerprint collection procedure	55
4.2	The posture of user measure the signal strength at a fingerprint location with a smartphone (mobile device) held by a tripod 1 m above the ground for measuring the fingerprint data at every allocated position	56
4.3	Ground floor plan of Building A where WLAN signals are measured. Location of fingerprint, measured online samples, AP locations, and origin measurement location coordinate are marked as shown in the legend	58
4.4	Ground floor plan of Building B where WLAN signals are measured. Location of fingerprint, measured online samples, AP locations, and origin measurement location coordinate are marked as shown in the legend	59
4.5	Ground floor plan of Building C where WLAN signals are measured. Location of fingerprint, measured online samples, AP locations, and origin measurement location coordinate are marked as shown in the legend	59
4.6	Floor plan of CRAWDAD dataset. The location of measurements and APs are marked according to the legend	61
4.7	Floor plan of Antwerp dataset with measured offline and online samples, AP locations, and origin coordinate of measurement locations	62

4.8	Floor plan of Dublin dataset. The offline and online measurement and AP locations are as marked.	63
4.9	Open space between floors in Building B	64
4.10	Path loss model of APs in Building A where (a) is the AP at Location (71.3, 37.7) in Floor 1, (b) is the AP at Location (9.4, 36.9) in Floor 3, and (c) is the AP at Location (68.4, 37.7) in Floor 4	70
4.11	Path loss model of APs in Building B where (a) is the AP at Location (16.5, 5.1) in Floor 3, (b) is the AP at Location (28.3, 5.2) in Floor 3, and (c) is the AP at Location (14.6, 5.1) in Floor 4	70
4.12	Path loss model of APs in Building C where (a) is the AP at Location (5.3, 13.6) in Floor 5, (b) is the AP at Location (32.6, 47.1) in Floor 6, and (c) is the AP at Location (5.9, 18.7) in Floor 7	71
4.13	Mean distance error plot of different k values of k NN algorithm in different environments	74
5.1	Mean distance error using univariate kernel algorithm versus number of selected APs for different AP selection algorithms in dataset (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	78
5.2	Percentage of distance errors within fingerprint spaces (two meters for Building A, B, C and Antwerp and one meter for CRAWDAD and Dublin dataset) versus number of selected APs in dataset (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	80
5.3	Mean of multi-floor distance error in multi-floor building environment versus number of selected APs for (a) Building A, (b) Building B, and (c) Building C	82
5.4	Percentage of multi-floor location accuracy within fingerprint spacing versus number of selected APs for (a) Building A, (b) Building B, and (c) Building C	82
5.5	Floor accuracy of multi-floor building versus number of APs of each AP selection algorithms in (a) Building A, (b) Building B, and (c) Building C	84

5.6	Mean error versus number of selected APs for single-floor localisation using different AP selection algorithms paired with multivariate kernel algorithm in (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	85
5.7	Accuracy within fingerprint spacing versus number of selected APs combined with multivariate kernel localisation algorithm in multi-floor environments of (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	86
5.8	Mean error versus number of selected APs for multi-floor localisation using different AP selection algorithms paired with multivariate kernel algorithm in (a) Building A, (b) Building B, and (c) Building C	87
5.9	Accuracy within fingerprint spacing versus number of selected APs of AP selection algorithms paired with multivariate kernel algorithm of multi-floor settings in (a) Building A, (b) Building B, and (c) Building C	88
5.10	Floor accuracy versus number of selected APs of AP selection algorithms paired with multivariate kernel algorithm of multi-floor settings in (a) Building A, (b) Building B, and (c) Building C	88
5.11	Mean error versus number of selected APs for single-floor localisation using different AP selection algorithms paired with k NN algorithm in (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	90
5.12	Accuracy within fingerprint spacing versus number of selected APs combined with k NN positioning algorithm in (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	91
5.13	Mean error versus number of selected APs for multi-floor localisation using different AP selection algorithms paired with k NN algorithm in (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	92
5.14	Accuracy within fingerprint spacing versus number of selected APs combined with k NN localisation algorithm in multi-floor environments of (a) Building A, (b) Building B, and (c) Building C	93

5.15	Floor accuracy of multi-floor building versus number of APs used by AP selection algorithms paired with <i>k</i> NN localisation algorithm in (a) Building A, (b) Building B, and (c) Building C	94
5.16	Mean distance error versus number of training sample at optimal AP numbers of the radio map database tested with univariate kernel algorithm in single-floor environment of (a) Building A, (b) Building B, and (c) Building C	96
5.17	Mean distance error versus number of training sample at optimal AP numbers of the radio map database tested with univariate kernel algorithm in multi-floor environment of (a) Building A, (b) Building B, and (c) Building C	96
5.18	Mean distance error versus number of training sample at optimal AP numbers of the radio map database tested with multivariate kernel algorithm in single-floor environment of (a) Building A, (b) Building B, and (c) Building C	97
5.19	Mean distance error versus number of training sample at optimal AP numbers of the radio map database tested with multivariate kernel algorithm in multi-floor environment of (a) Building A, (b) Building B, and (c) Building C	97
5.20	Mean distance error versus number of training sample at optimal AP numbers of the radio map database tested with <i>k</i> NN algorithm in single-floor environment of (a) Building A, (b) Building B, and (c) Building C	98
5.21	Mean distance error versus number of training sample at optimal AP numbers of the radio map database tested with NN algorithm in multi-floor environment of (a) Building A, (b) Building B, and (c) Building C	99
5.22	The plot of error within upper 95% of mean error confidence limit (error 3.7 m) of univariate kernel of single-floor localisation in Building A	101
5.23	Percentage of AP reduction compared to by AP selection algorithms compared to localisation algorithm without AP selection in single-floor setting	103
5.24	Percentage of AP reduction compared to by AP selection algorithms compared to localisation algorithm without AP selection in multi-floor setting given (a) Building A,	105

	(b) Building B, and (c) Building C	
5.25	Processing time of AP techniques versus number of selected APs in single-floor dataset of (a) Building A, (b) Building B, and (c) Building C. The selected APs are processed with univariate kernel localisation algorithm	109
5.26	Processing time of AP techniques versus number of selected APs in multi-floor dataset of (a) Building A, (b) Building B, and (c) Building C. The selected APs are processed with univariate kernel localisation algorithm	109
6.1	CDF of number of floor error on each tested building of (a) Building A, (b) Building B, and (c) Building C	113
6.2	Per floor analysis of all tested algorithms in all buildings of (a) Building A, (b) Building B, and (c) Building C	116
6.3	Average algorithm processing time for each tested floor detection algorithm in (a) Building A, (b) Building B, and (c) Building C	118
6.4	Effect of different number of measurement samples to the accuracy of floor detection by the floor localisation algorithms in (a) Building A, (b) Building B, and (c) Building C	119
6.5	Effect of floor accuracy estimated by AKF and KLF algorithms when Max Kernel AP selection algorithm is applied to the cluster according to different number of AP in (a) Building A, (b) Building B, and (c) Building C	120
7.1	Mean error variation by using different k and ϖ in all six environments: (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin. The lowest mean error is marked with black unfilled circle	124
7.2	Different values of σ versus mean positioning error in all tested environments	125
7.3	Cumulative density function of mean errors of tested horizontal positioning algorithms using six environment datasets (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin. In Antwerp environment, errors of multiclass k NN classifier and its kernel version are overlapped	127
7.4	Localisation accuracy within fingerprint spacing of each tested horizontal localisation algorithm in (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	129

7.5	Effect of reducing the number of training samples for all localisation algorithms. The normal and kernel k NN classifier algorithms are tested in three different versions using different value of ϖ . The plot of $MkNN(\text{best } \varpi)$ and $MKkNN(\text{best } \varpi)$ are overlapped	131
7.6	Effect of reducing number of APs based on average signal strength value at each fingerprint location for all tested algorithms in all environments of (a) Building A, (b) Building B, (c) Building C, (d) CRAWDAD, (e) Antwerp, and (f) Dublin	134
7.7	Mean error of both NN classifier algorithms at different number of selected APs when combined with Max Kernel AP selection algorithm in (a) Building A, (b) Building B, and (c) Building C	135
8.1	Multi-floor mean errors of multi-floor algorithms tested in (a) Building A, (b) Building B, (c) Building C	138
8.2	Localisation accuracy within fingerprint spacing of Marques, Gansemer, and proposed multi-floor location algorithm in (a) Building A, (b) Building B, and (c) Building C	139
8.3	Processing time of each multi-floor localisation algorithm in (a) Building A, (b) Building (b), and (c) Building C	140
B1.1	Building A	154
B1.2	Building B	154
B1.3	Building C	155
B1.4	Antwerp. The measurements are made at the seventh floor level of the building (top most floor) of the building as marked in red colour.	155
B1.5	Dublin	156
B2.1	Floor plan of Building A where WLAN signals are measured. Location of fingerprint, measured online samples, AP locations, and origin location coordinate of the measurement are marked as shown in the legend. The location according to the floor levels are (a) first, (b) second, (c) third, and (d) fourth	158

B2.2	Floor plan of Building B where WLAN signals are measured. Location of fingerprint, measured online samples, AP locations, and origin measurement location coordinate are marked as shown in the legend. The location according to the floor levels are (a) first, (b) second, (c) third, (d) fourth, (e) fifth, (f) sixth, (g) seventh, (h) eighth, (i) ninth, and (j) tenth. The area marked with VOID is the open spaces between floors	161
B2.3	Floor plan of Building C where WLAN signals are measured. Location of fingerprint, measured online samples and AP locations are marked as shown in the legend. The location according to the floor levels are (a) first, (b) second, (c) third, (d) fourth, (e) fifth, (f) sixth, and (g) seventh	164

LIST OF ABBREVIATIONS

AKF	Averaged Kernel Floor
ANN	Artificial Neural Network
AP	Access Point
CDF	Cumulative Density Function
FAF	Floor Attenuation Factor
GNSS	Global Navigation Satellite Service
IRLS	Iterative Reweighted Least Square
KDE	Kernel Density Estimate
KLF	Kernel Logistic Floor
KLPD	Kernel Logistic Pairwise Discriminant
KLR	Kernel Logistic Regression
kNN	k-Nearest Neighbour
LBS	Location-Based Service
LDA	Linear Discriminant Analysis
MAC	Media Access Control
MAP	<i>Maximum A Posteriori</i>
NLL	Negative Likelihood
NLOS	Non-Line of Sight
OVA	One-Versus-All
OVO	One-Versus-One
RBF	Radial Basis Function
RF	Radio Frequency
RSS	Received Signal Strength
SVM	Support Vector Machine
UPM	Universiti Putra Malaysia
WLAN	Wireless Local Area Network
AKF	Averaged Kernel Floor
ANN	Artificial Neural Network
AP	Access Point
CDF	Cumulative Density Function
FAF	Floor Attenuation Factor
GNSS	Global Navigation Satellite Service
IRLS	Iterative Reweighted Least Square
KDE	Kernel Density Estimate
KLF	Kernel Logistic Floor
KLPD	Kernel Logistic Pairwise Discriminant
KLR	Kernel Logistic Regression
kNN	k-Nearest Neighbour
LBS	Location-Based Service
LDA	Linear Discriminant Analysis
MAC	Media Access Control
MAP	<i>Maximum A Posteriori</i>
NLL	Negative Likelihood
NLOS	Non-Line of Sight
OVA	One-Versus-All
OVO	One-Versus-One
RBF	Radial Basis Function
RF	Radio Frequency

RSS	Received Signal Strength
SVM	Support Vector Machine
UPM	Universiti Putra Malaysia
WLAN	Wireless Local Area Network



LIST OF SYMBOLS

$\arg \max_{\xi} p(.)$	Maximum A Posteriori estimate of ξ
$\mathbf{A}_v$	Pairwise APs signal vector of v -th combination in the radio map database
$\mathbf{A}_{\beta}$	Pairwise APs signal vector of β -th combination in the online sample
AP_l	l -th access point
$\hat{c}$	Estimated cluster/floor
c_f	f -th cluster
D_i	Signal distance of i -th fingerprint
$D_{\beta i}$	Nearest signal distance of kNN classifier at i -th fingerprint location
$diag[.]$	Diagonal matrix function
$\mathbf{F}(\mathbf{p}_i)$	Fingerprint element at i -th location
h	Adjustable similarity parameter of Kernel Density Estimate
i	Fingerprint/Location index
k	Number of nearest estimated location
$\mathbf{K}(\cdot)$	Kernel function
$NLL(\cdot)$	Negative likelihood function of logistic regression
$\hat{p}_{x\xi}$	Estimated x-coordinate location
$\hat{p}_{y\xi}$	Estimated y-coordinate location
$\hat{\mathbf{p}}$	Estimated location
$\mathbf{p}_i$	Location of i -th fingerprint
$p(\cdot)$	Probability function
$P_r(d_0)$	RSS at reference distance d_0 from an AP
$p_{x\xi}$	Actual x-coordinate location
$p_{y\xi}$	Actual y-coordinate location
$P_r(d)$	RSS at a fingerprint location of d distance from an AP
q	Location index of the AP l signal grouped in the cluster c_f
$\mathbf{r}$	Vector of pairwise APs signal data
$RSS_{AP_l}(d_{AP_l})$	Received Signal Strength of AP_l at a distance d from the AP
$RSS_{AP_l}(d_0)$	Received Signal Strength of AP_l at a reference distance d_0
$S_{\beta i}$	Averaged of ϖ minimum $D_{\beta}(\psi_{\omega i})$ signal distance of i -th fingerprint location of k NN classifier
$\mathbf{T}$	Transpose function
T	Total number of samples measured at one fingerprint location
U	Total number of points of signal range to determine the kernel in density estimate

$\mathbf{w}$	Model parameter vector of the logistic function
y	Class/Location of vector pairwise signal data $\mathbf{r}$
Ω_i	i -th class/location averaged $D_{\beta i}$ or $S_{\beta i}$ signal distance of test sample AP combination
$\boldsymbol{\varphi}_i$	Offline signal vector of i -th fingerprint
Δf_{neigh}	Difference between two neighbouring kernel u and $u + 1$
Ξ	Total number of location estimation
Φ	Total class labels or total number of vector signal data existed in both classes
ξ	Index of location estimation
η_{AP_l}	Path Loss Exponent referring to AP_l signals
η_{SF}	Similar floor path loss exponent
ρ	Number of class label from total of Φ
ϖ	Number of nearest minimum signal distance of each fingerprint location of k NN classifier
$\boldsymbol{\varphi}$	Online measured signal vector
γ	Adjustable similarity parameter of kernel function

CHAPTER 1

INTRODUCTION

1.1 Overview

Location is one of the most valuable information in mobile communication nowadays. Today's mobile devices are designed and programmed to have location features so it can be complemented with Location-Based Service (LBS) applications (Schiller and Voisard 2004). The location is important because it reflects interaction and context of the user based on the location of the device. In past times, location is mainly used to guide users to move from one place to another by giving the best possible route to reach the destination. However currently, the location information is used in much wider context. For example, by using smartphone a user can locate user's current position and share the location with his or her friends on the social network. Also, a user can book a taxi service or finding the nearest restaurants or cash machines by considering user's current location.

Unfortunately, all of these applications infer the device location mainly based on its position in outdoor environment which mainly depends on the information provided by Global Navigation Satellite System (GNSS) receiver integrated with the mobile device. However, with only information of outdoor location, further development or enhancement of LBS applications is restricted. In near future, LBS applications are designed and developed to work for indoor-based services. For example, to assist shoppers to find items that they want to purchase by locating the exact aisle of the item in a hypermarket, to help drivers find their car in a multi-story indoor airport car park, and to supply information for smart building administrators to monitor temperature, room availability, and lightings. Therefore it is a requirement to know accurate indoor location to achieve these objectives. GNSS receiver however is generally not suitable to provide indoor location due to blockage and attenuation of the signals by roofs, walls and other objects.

Researchers have been working to find alternative technologies to obtain accurate indoor location information. Some solutions includes Wireless Local Area Network (WLAN) infrastructure (Fang and Lin 2010, Prieto et al. 2012, Mirowski et al. 2014, Wang et al. 2015, Liang, Zhang, and Peng 2015), infrared (Petrellis, Konofaos, and Alexiou 2006, Tao et al. 2014), and Bluetooth (Hossain and Soh 2007, Jianyong et al. 2014, Gu and Ren 2015). Among the solutions, one of the most promising solutions is WLAN as its signal coverage is available almost anywhere in urban environments. Indoor localisation methods based on WLAN are largely documented in the literature and surpass any other indoor localisation technologies.

1.2 WLAN Indoor Localisation

Indoor localisation based on WLAN was pioneered by Bahl and Padmanabhan (2000). WLAN based localisation is established by associating received Radio Frequency (RF) signals with physical location. The received RF signals or also known as Received Signal Strength (RSS) could characterise different locations as the propagated signals are location dependent. To localise unique location, RSS is measured throughout the floor area as combination of multiple signals from multiple Access Points (APs).

The location estimation technique could be classified by two methods; radio propagation based model and fingerprinting method. In radio propagation based model, the location is estimated by triangulation where the location of three or more access points must be known and the path loss model such as log-distance, which described the environment dependent relationship of the distance between the transmitter (AP) and receiver (device) according to variation of signal strength value, of the APs are determined. During position request by the device, the signal vector measured by the device at an unknown location is used as the input to the path loss model to determine the distance of the device from the APs which translates the location of the device. On the other hand, the fingerprinting method first requires real surveying by collecting the signal signature at every unique physical location which is also called as fingerprint location. The collection of multiple signal signatures associated with the physical locations are stored in the database as radio map and during the location request by the device, the signal vector of the device is compared its similarity with the one in the database to determine the location.

Between the two methods, the latter technique, fingerprinting, is preferred. This is because higher positioning accuracy could be achieved compared to radio propagation based model. Radio propagation based model could not provide finer accuracy due to inability of the model to characterise complex multipath signals received at each specific locations. However, fingerprinting technique comes with the cost of high processing time of localisation algorithm due to large amount of signal signatures in the radio map. In today's application, indoor localisation system should be embedded in mobile device such as smartphone which has small computing capability, the localisation algorithm must be designed and developed to utilise as small processing power as possible and at the same time retain good positioning accuracy. Some examples of good and robust classical localisation algorithms are k -Nearest Neighbour (k NN) (Bahl and Padmanabhan 2000), univariate kernel (Roos et al. 2002), and multivariate kernel (Kushki et al. 2007). Additionally, the localisation algorithm must be designed so that it can work in multiple indoor environments especially in urban area where the application is demanded. Generally, these areas are occupied with various multi-floor constructions. Therefore, the indoor localisation system must be designed and developed for this kind of infrastructure.

1.3 Multi-Floor Localisation

Numerous studies can be found on development of indoor localisation system. However, majority of them are focussing on single-floor localisation (Wu et al. 2013, Sorour et al. 2015, Chen and Wang 2015). It is investigated that the research on multi-floor localisation receives less attention is mainly due to two reasons. First, large radio map datasets is required as multi-floor data must be collected e.g. large fingerprint dataset for fingerprinting method, or large AP location dataset for AP based method. Second, the perception that development of multi-floor localisation could be easily extended from single-floor localisation technique. However, multi-floor WLAN localisation is actually much more challenging compared to single floor localisation. Figure 1.1 illustrates the comparison between single-floor localisation and multi-floor localisation. It is understood that multi-floor localisation challenges comes additional floor environment which increases the complexity of localisation in multi-floor setting.

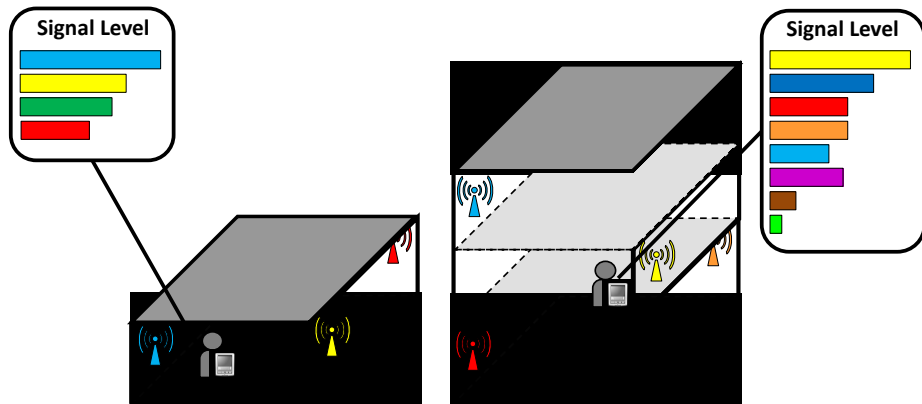


Figure 1.1. WLAN indoor localisation in single-floor and multi-floor settings

There are significant differences between multi-floor and single-floor WLAN localisation. First, the datasets of the collected signal data must be characterised by three-dimensional position, which includes floor level of the building and horizontal positions of the data compared to only horizontal positions required for single-floor localisation. As the amount of entries in the radio map varies according to the number of fingerprint locations, therefore the amount of entries of the datasets for multi-floor localisation is generally in multiplication of the number of fingerprint locations and number of floor level exists within the building. Second, the number of APs increases proportionally with the number of floor level in multi-floor building. This causes the dimensionality of AP during online phase increase. Additionally, during the signal measurement process, each signal vector for multi-floor localisation will be added with multiple APs signal from other floors in addition to signal from the APs on the floor itself compared to single-floor where the AP signals mostly come from the APs installed on the floor. The computation of the localisation algorithms depends on

the three factors which are number of fingerprint locations, number of APs within the environment and the size of signal vector and these are the elements that are mentioned in first, second, and third comparisons. Therefore the computational complexity or processing time of the algorithm in multi-floor setting will be much higher compared to single-floor localisation. The fourth difference is the estimated locations in multi-floor environment require additional coordinate of the floor level or the z-coordinate compared to single-floor environment which is described by only x and y-coordinate. Lastly, the probability of error in multi-floor localisation is generally higher because of possibility that the estimated location is in different floor level than expected. All of these comparisons are summarised in Table 1.1.

Multi-floor localisation system could be divided into two main problems which are to locate the floor level of the device and to position the device on the chosen floor level which determines the horizontal location. The algorithms should be accurate and quickly processed the radio map database to give estimation of the location. Therefore, three important categories that should be investigated in order to produce an efficient multi-floor location are radio map fingerprint database optimisation, floor localisation algorithm, and horizontal localisation algorithm.

1.4 Kernel and Multi-Class Classifier Approach for Multi-Floor Localisation

In particular, the technique to estimate the location in multi-floor environment has been focusing on similar type of algorithm. The algorithm also is the extension of previously developed algorithm for single-floor localisation. Multi-floor localisation involves processing larger database compared to single-floor and therefore the extended algorithm is no longer suitable to be applied for multi-floor case. The usage of classical algorithms in multi-floor environment also leads to increasing computational complexity as related to increasing amount of database element. To solve the problem, this thesis proposes new multi-floor localisation technique based on kernel and multi-class classifier. The techniques implements kernel density estimate and multi-class classifier based on logistic regression as tools for AP selection, and floor localisation algorithm. The k NN multi-class classifier is applied for new horizontal localisation algorithm. Theoretical foundation and algorithm implementation of the technique is described in details in Chapter 3 and 4 respectively.

Table 1.1. Summary of differences between single-floor WLAN localisation versus multi-floor WLAN localisation

Issue	Single Floor Localisation	Multi-Floor localisation
Radio map database	Radio map database is for single floor and the quantity of the entries of the database depends on the number of fingerprint locations.	Radio map database is in multiple number of floors exist in the building and the entries generally consists of multiplication of number of fingerprint locations and number of floor level.
Dimensions of AP	Dimensionality of AP depends on the number of APs installed in single floor.	Dimensionality of APs increase with increasing number of APs installed on every floor level of the building.
Fingerprint signal vector	Signal vector at each fingerprint location is majorly from multiple APs that are installed on the floor level and the signal follows normal path loss model.	Signal vector at each fingerprint location consists of signal from APs within similar floor level and also from other floor level within the building and the signal follows multi-floor path loss model.
Estimated location coordinate dimension	Estimated location is in 2 dimensional coordinate (x and y) which is the horizontal location.	Estimated location is in 3 dimensional coordinate (x, y, and z) which includes floor location and horizontal location.
Probability of location error	The probability of location error is only within horizontal locations.	The probability of location error may increase due to possibility of estimated location is located on different floor level than expected.

1.5 Problem Statement

To develop an efficient multi-floor localisation system, all of the elements of multi-floor localisation in Table 1.1 should be analysed according to categories mentioned above. There have been some developments of multi-floor WLAN localisation system and comprehensive review on the topic is written in Chapter 2 of this thesis. From the review, it is indicated that majority of multi-floor WLAN localisation algorithm are developed based on extension of single-floor localisation algorithms. Generally, the problem with this kind of system did not consider computational complexity of the algorithms implemented in multi-floor environment. Also, the algorithm is not optimised for simultaneous estimation of both floor and horizontal locations. Specifically, in order to develop an efficient and robust multi-floor indoor localisation system, this thesis investigates the following problems:

1. Majority of the proposed floor localisation algorithm is still based on classical similarity measure algorithm which is extended for multi-floor localisation. This means the developed floor localisation algorithm requires calculating every single entry of fingerprint to perform floor estimation. As discussed in Section 1.3, the multi-floor building problem involves the number of fingerprints is in the multiple of number of floor

level exists inside the building. Therefore the computational complexity increases as the number of floor increases.

2. Considering all APs for localisation may degrade the performance of the localisation system. The number of APs installed within building increases as the number of floor level increases so that the coverage of the signal is enough for localisation system to work. This leads to AP dimensionality in multi-floor environment is much higher compared to single floor.
3. The horizontal localisation algorithm in multi-floor setting is mainly implemented based on previously developed algorithm for single-floor problem. However in multi-floor building, additional AP signals are measured from other floor levels which degrade the performance of the algorithm. Consequently, the location estimation error in multi-floor location could not be minimised compared to single-floor location if similar algorithm is implemented for both environments.
4. The validity of some existing multi-floor localisation algorithm is questionable as the algorithms are only tested in limited testing area such as one or two buildings and the buildings are low rise which contains less than five floor levels, and it is not guaranteed that the proposed algorithm will produce the similar performance as in different environments.
5. The work on combining radio map database optimisation, floor localisation and horizontal localisation is not well studied to improve the multi-floor localisation system. Existing techniques are based solely on either improving floor localisation only or combination of database optimisation and floor localisation. The performance of combining all of the techniques is unknown.

1.6 Objective of the Research

The aim of this thesis is to develop a robust and efficient multi-floor localisation system emphasizing on: i) the accuracy of the localisation algorithms in both vertical and horizontal position which are characterised by estimated location error of the algorithms, and ii) the computational complexity of localisation algorithm which is to reduce the processing time of the developed algorithms. To achieve the aim, detail objectives are given as follows:

1. To optimise the radio map database by implementing AP selection technique to limit or reduce the number of required APs information to perform localisation and at the same time retain similar accuracy with using all APs information. Two novels AP selection algorithms are introduced to improve the selection of APs in optimising the database. The performances of the proposed AP selection schemes are compared with existing AP selection technique to evaluate the performance of the

proposed algorithms based on three classical localisation algorithms of k NN, univariate kernel, and multivariate kernel.

2. To reduce the processing complexity of floor localisation algorithm and at the same time to improve the accuracy of the estimated floor level. Proposed two new floor localisation algorithms based on clustered multi-floor radio map. The performances of the new floor localisation algorithms are compared with existing floor localisation algorithms to evaluate the effectiveness of the algorithm.
3. To improve the location estimation error of horizontal localisation algorithm by introducing novel localisation algorithms for both multi-floor and single-floor environments. The horizontal localisation algorithms are compared with classical single-floor localisation algorithms (k NN, univariate kernel, and multivariate kernel) and the performances of all algorithms are analysed and discussed.
4. To combine the proposed AP selection technique, floor localisation algorithm and horizontal localisation algorithms to evaluate performance in multi-floor environment. The test is in multiple multi-floor environments with different number of floor levels to verify the performance of the proposed algorithm. The performance is also compared with existing multi-floor localisation algorithm.

1.7 Organisation of the Thesis

In Chapter 2, review of the literature on the multi-floor localisation system is given. The review presents in depth study on problems exist in existing multi-floor localisation system which leads to the development of problem statement in Section 1.5. The review identifies the gaps in current research particularly in multiple scenarios of multi-floor e.g. validity of chosen environment for testing the multi-floor localisation system, radio map database optimisation techniques, floor localisation algorithms, and lastly the horizontal localisation algorithms.

Chapter 3 first presents the background on WLAN fingerprint localisation and theory that is related to localisation algorithm used in this thesis and second describes the novel algorithms developed for the multi-floor localisation. The state-of-the-art WLAN fingerprint localisation mechanism is introduced. The related improvement components of the multi-floor localisation are presented which involves the database optimisation, floor localisation, and horizontal localisation. The theory of three popular classical algorithms which are used as benchmark for proposed algorithms are also discussed. The theory on kernel density estimate and machine learning multiclass classification using k NN and logistic regression are explained. The theories are applied for the following proposed algorithms. The database optimisation algorithms implement Max Kernel and Kernel Logistic Pairwise Discriminant (KLDPD). The floor localisation

comprises of Averaged Kernel Floor and Kernel Logistic Floor algorithms. Normal and kernel multi-class k NN algorithms are used for horizontal localisation

Chapter 4 explains the measurement setup of collecting the RSS signal data. This includes the measurement tools, floor map, and specification of the measurement. Also the method to extract the path loss parameters of the measured signal data to be tested with propagation model is shown. The details of measured fingerprint database specification and evaluation of path loss model using extracted path loss parameter of the measured signal data from the database are described. The performance metrics to evaluate the developed algorithms are discussed. Additionally, the method to determined number of k used for k NN algorithm is presented.

Chapter 5 to 8 discuss the results related to the developed multi-floor system. The results explain the performance of the proposed AP Selection (Chapter 5), floor localisation (Chapter 6), and horizontal localisation algorithms (Chapter 7) of which results are evaluated and discussed. The results of combining the three proposed algorithms for multi-floor localisation are explained in Chapter 8. The results are mainly focusing on accuracy and computational complexity of the algorithms.

Lastly, Chapter 9 draws conclusion on the proposed multi-floor system. The work presented in the thesis is summarised. The contributions of the thesis are highlighted. Also, further research directions are suggested.

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