



Unsupervised Indoor Localization (UnLoc)

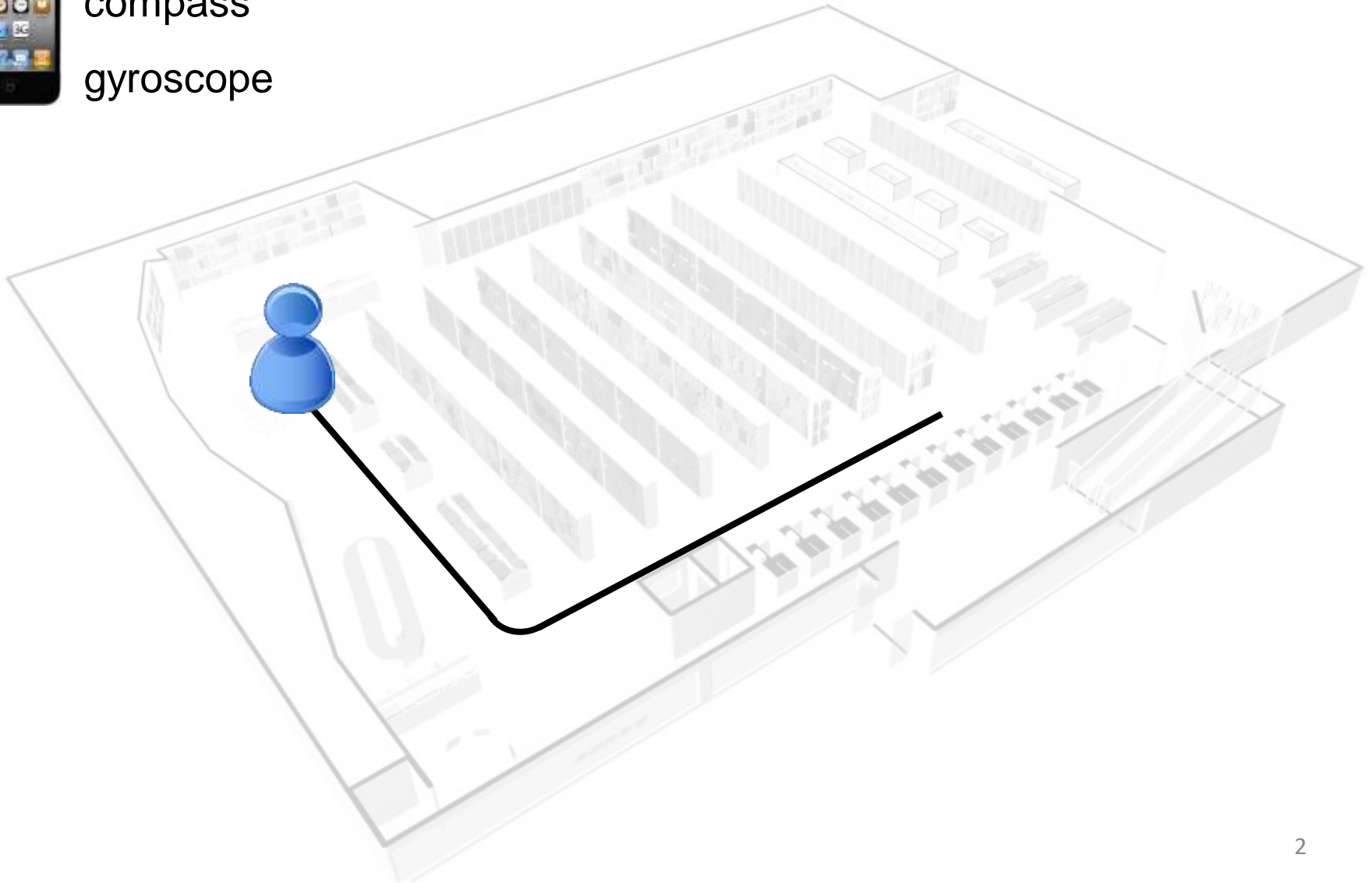
Pedestrian Dead Reckoning (PDR)



accelerometer

compass

gyroscope



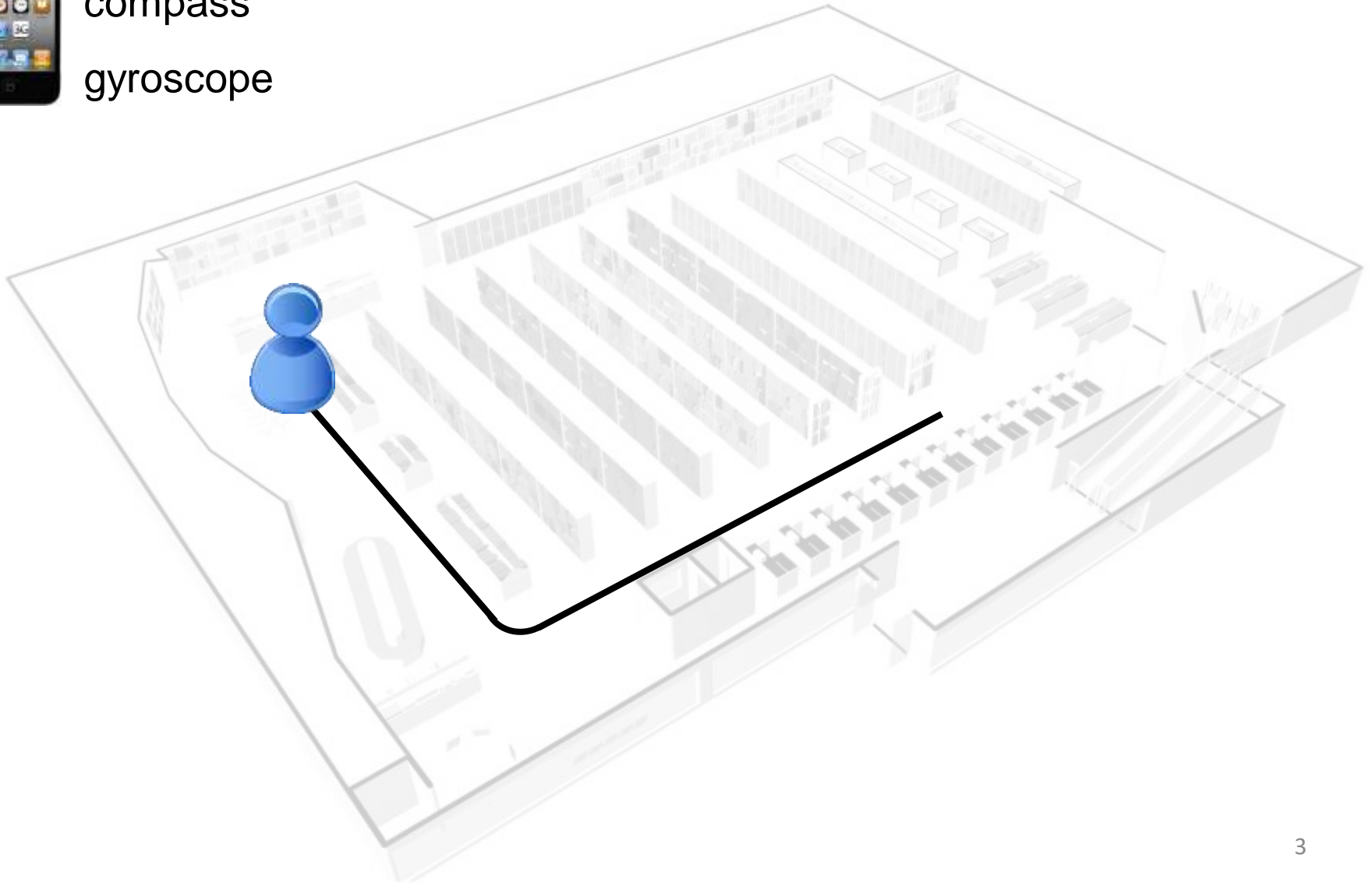
Pedestrian Dead Reckoning (PDR)



accelerometer

compass

gyroscope



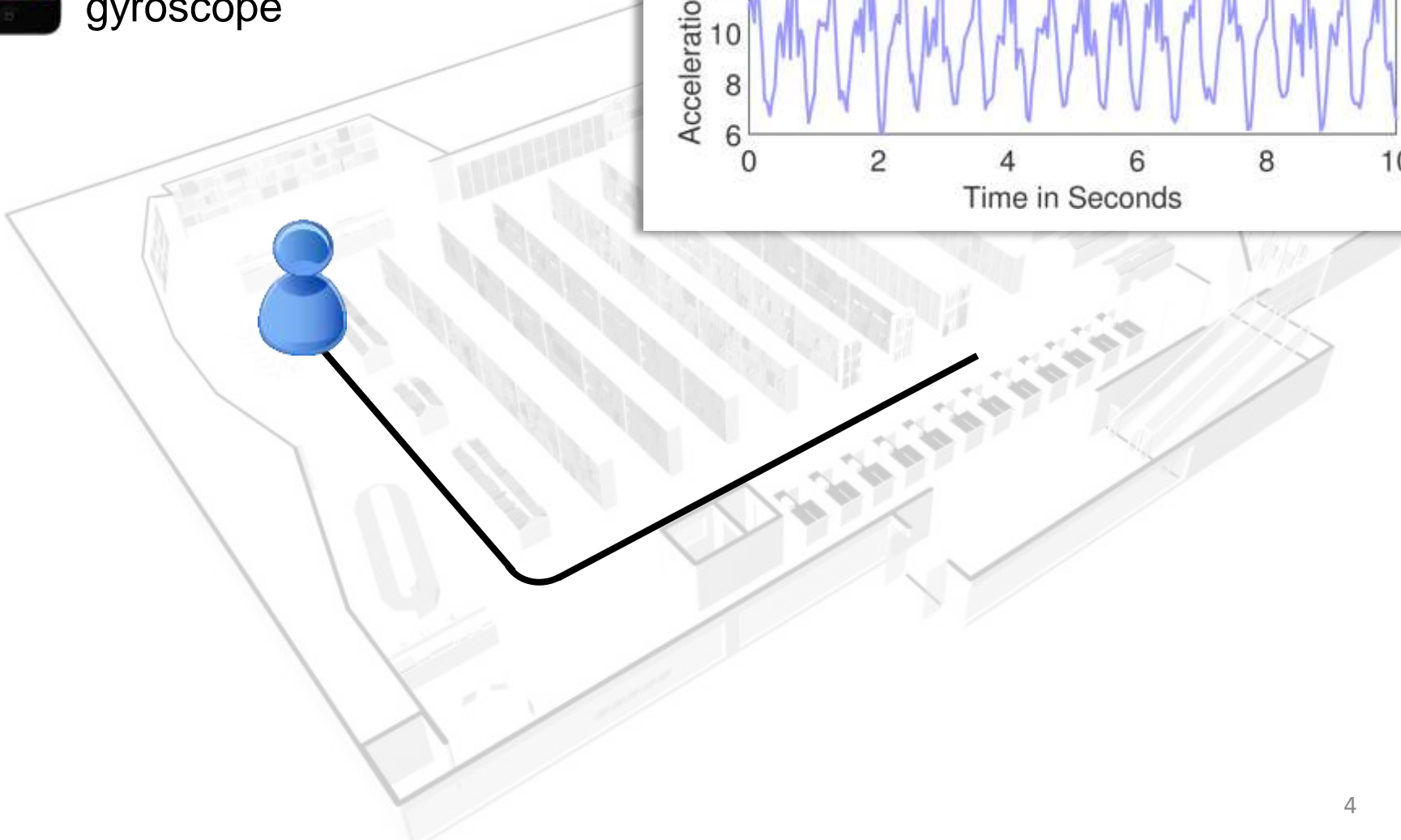
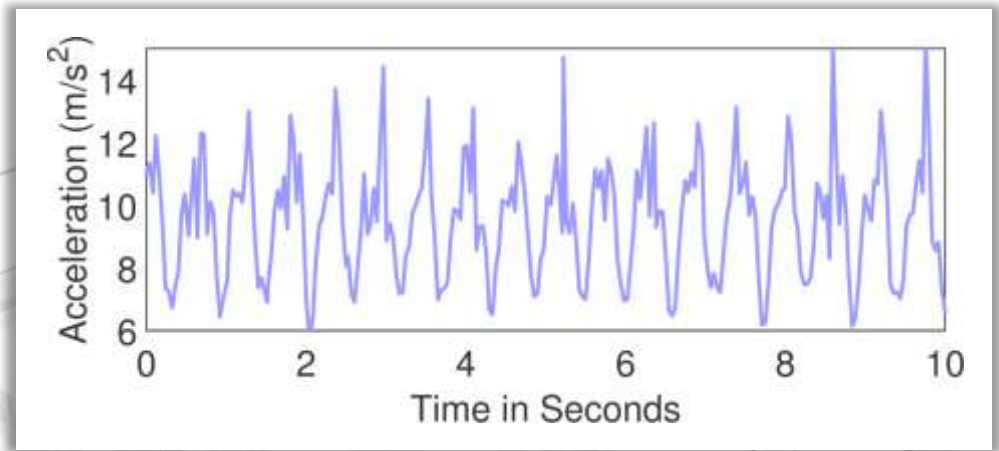
Pedestrian Dead Reckoning (PDR)



accelerometer

compass

gyroscope



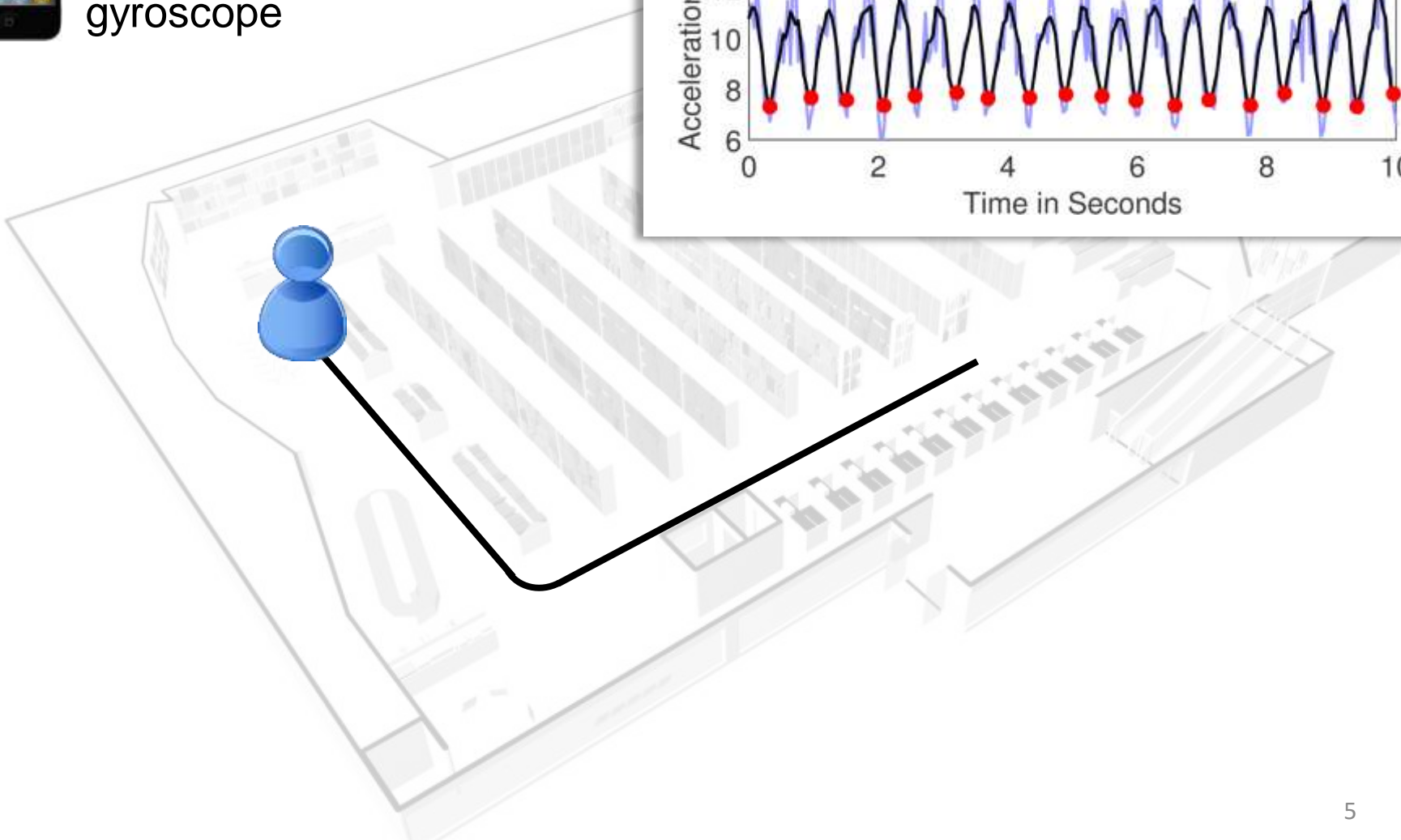
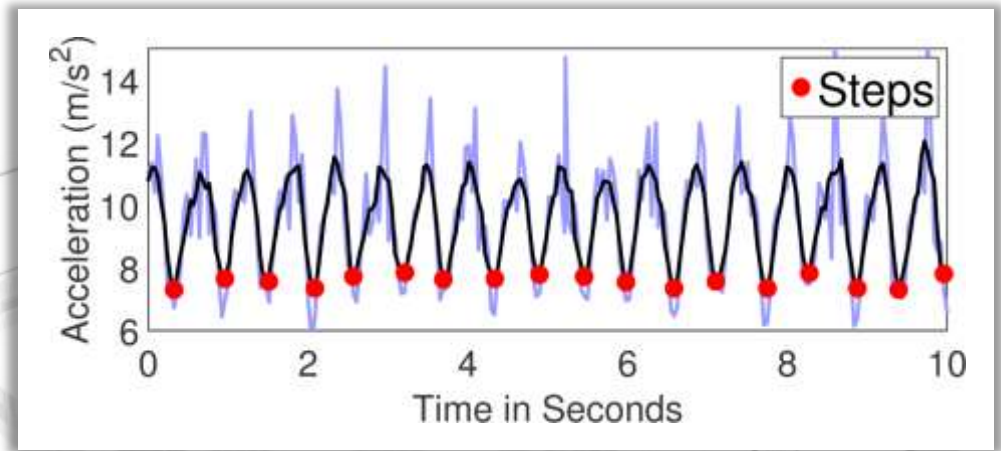
Pedestrian Dead Reckoning (PDR)



accelerometer

compass

gyroscope



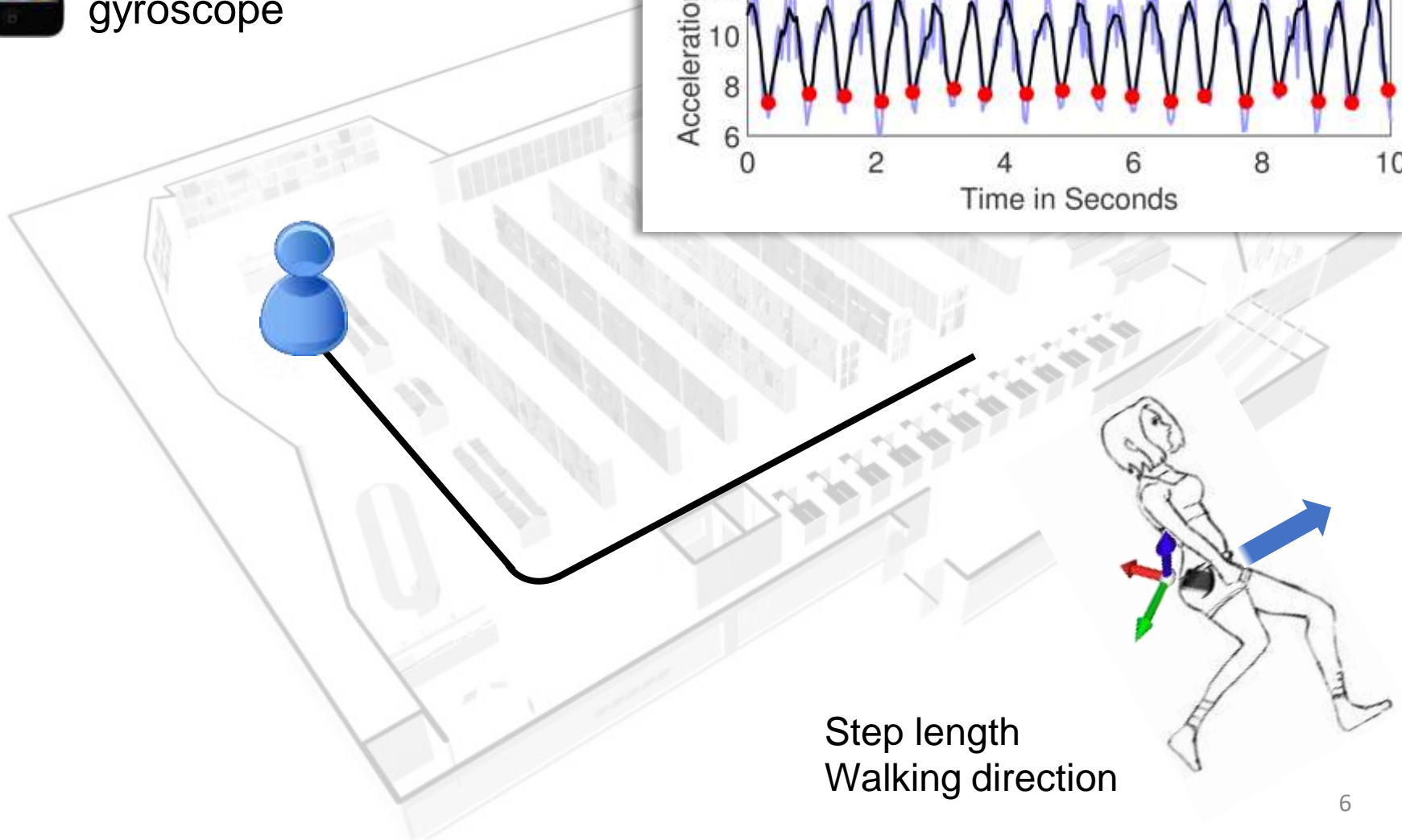
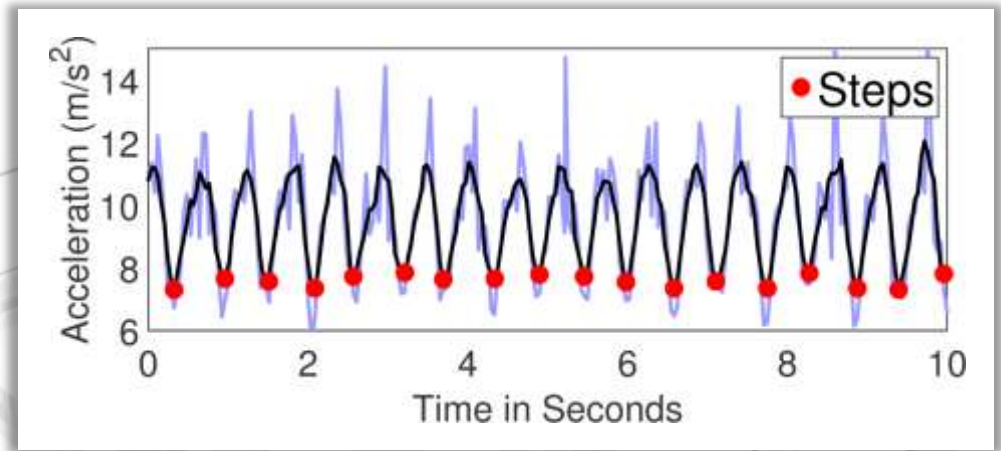
Pedestrian Dead Reckoning (PDR)



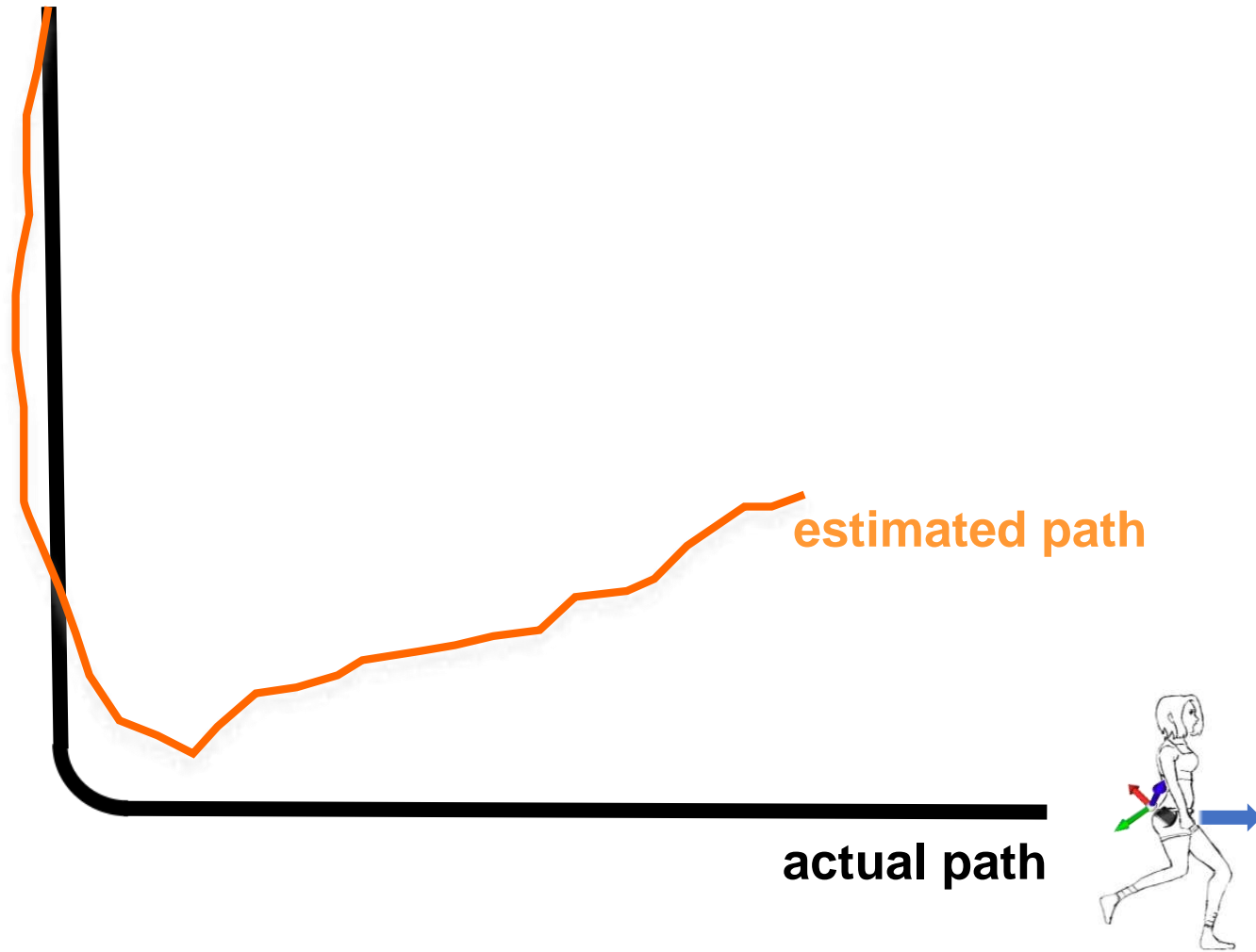
accelerometer

compass

gyroscope



Pedestrian Dead Reckoning (PDR)





Charles Lindbergh landed in Paris from New York.

No GPS

He used dead reckoning and **obtained fixes from the stars.**

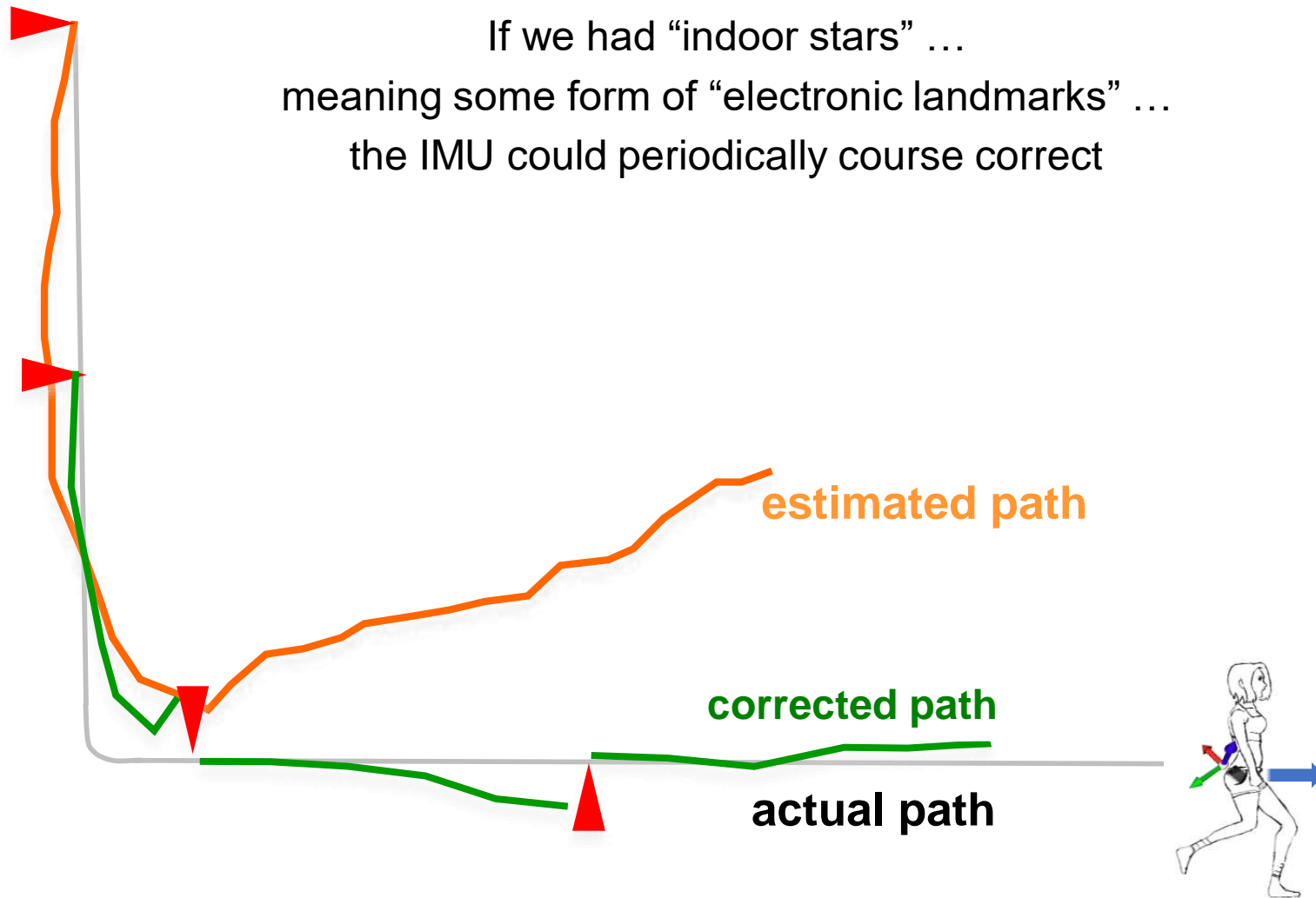


Pedestrian Dead Reckoning (PDR)

If we had “indoor stars” ...
meaning some form of “electronic landmarks” ...
the IMU could periodically course correct

Pedestrian Dead Reckoning (PDR)

If we had “indoor stars” ...
meaning some form of “electronic landmarks” ...
the IMU could periodically course correct



If we had “indoor stars” ...
meaning some form of “electronic landmarks” ...
the IMU could periodically course correct

Idea

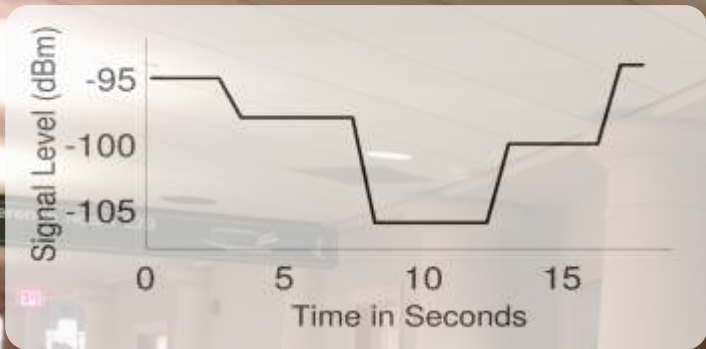
If sensor data about the ambience embed natural patterns in them,
can these patterns be viewed as landmarks ...
and can those landmarks be used for PDR course correction



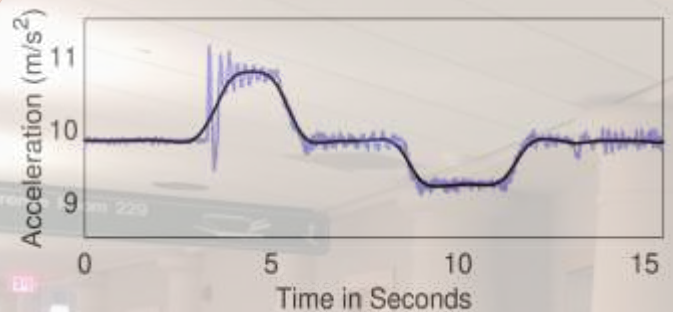
Unsupervised Localization (UnLoc)

Automatically identify sensor landmarks and recalibrate IMU errors

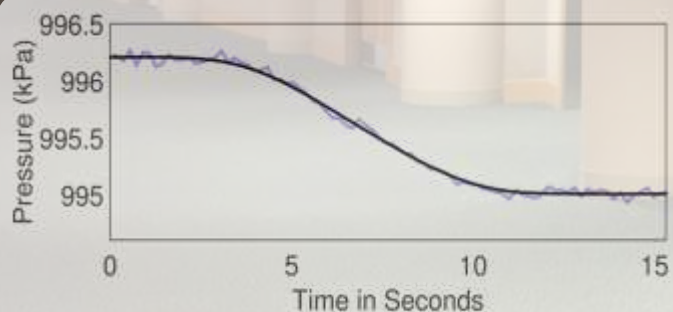
Cellular pattern



Acceleration pattern



Pressure change



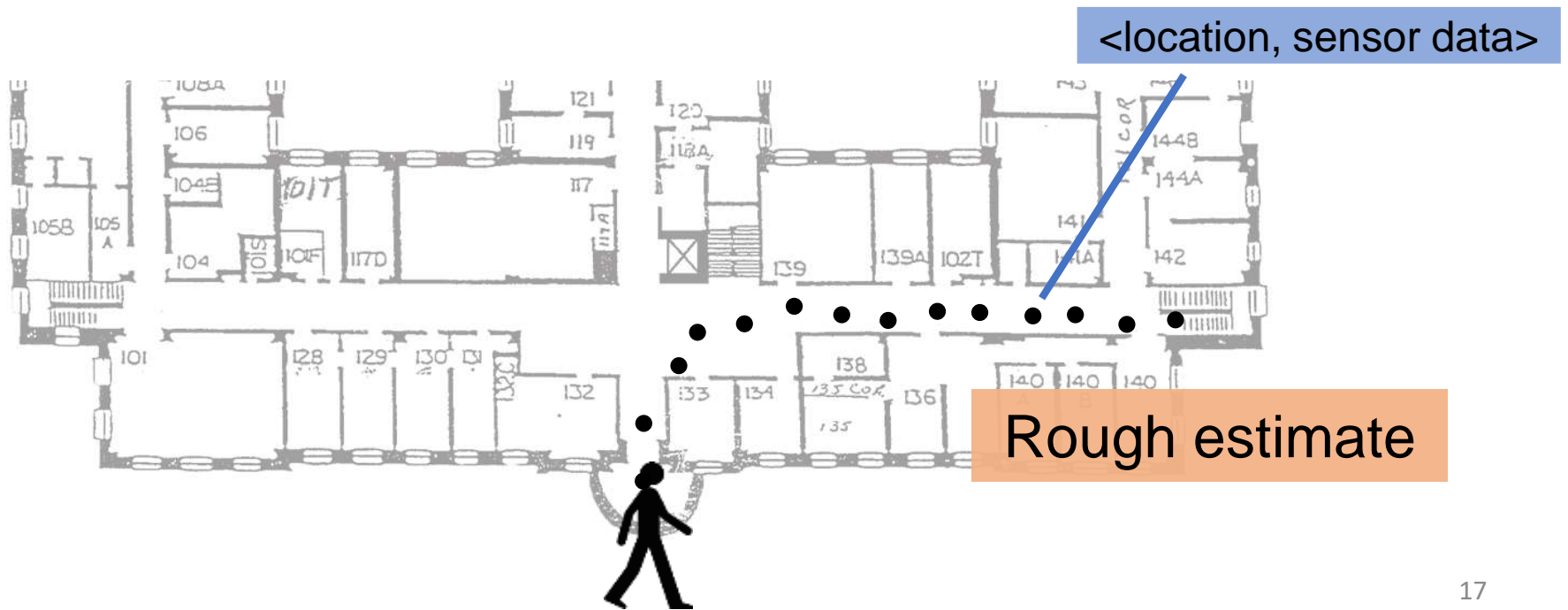
3 step iterative algorithm

1. Detect landmarks (from ambient sensing)
2. Estimate rough landmark locations (from rough PDR and multiple measurements)
3. Localize users from landmarks and refine landmarks from users (iterate until convergence)



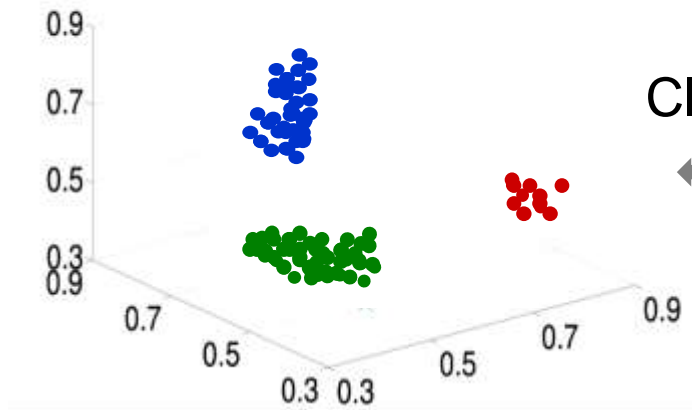
1. How to **automatically** detect **landmarks**

Raw Sensor → Landmarks



Raw Sensor → Landmarks

sensor space

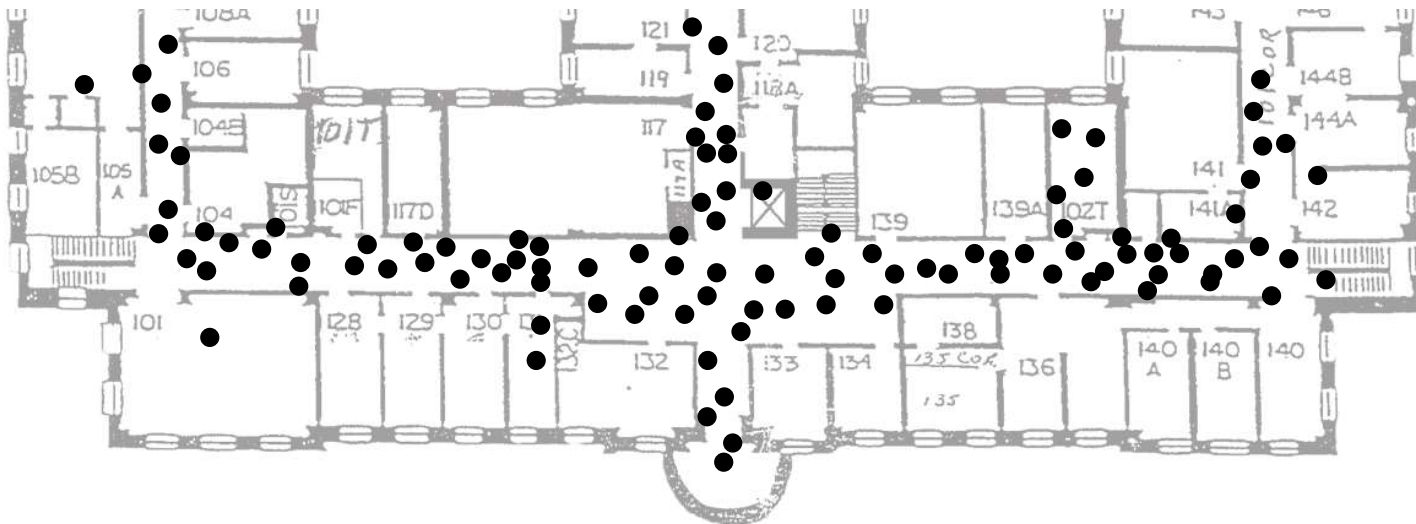


Clustering

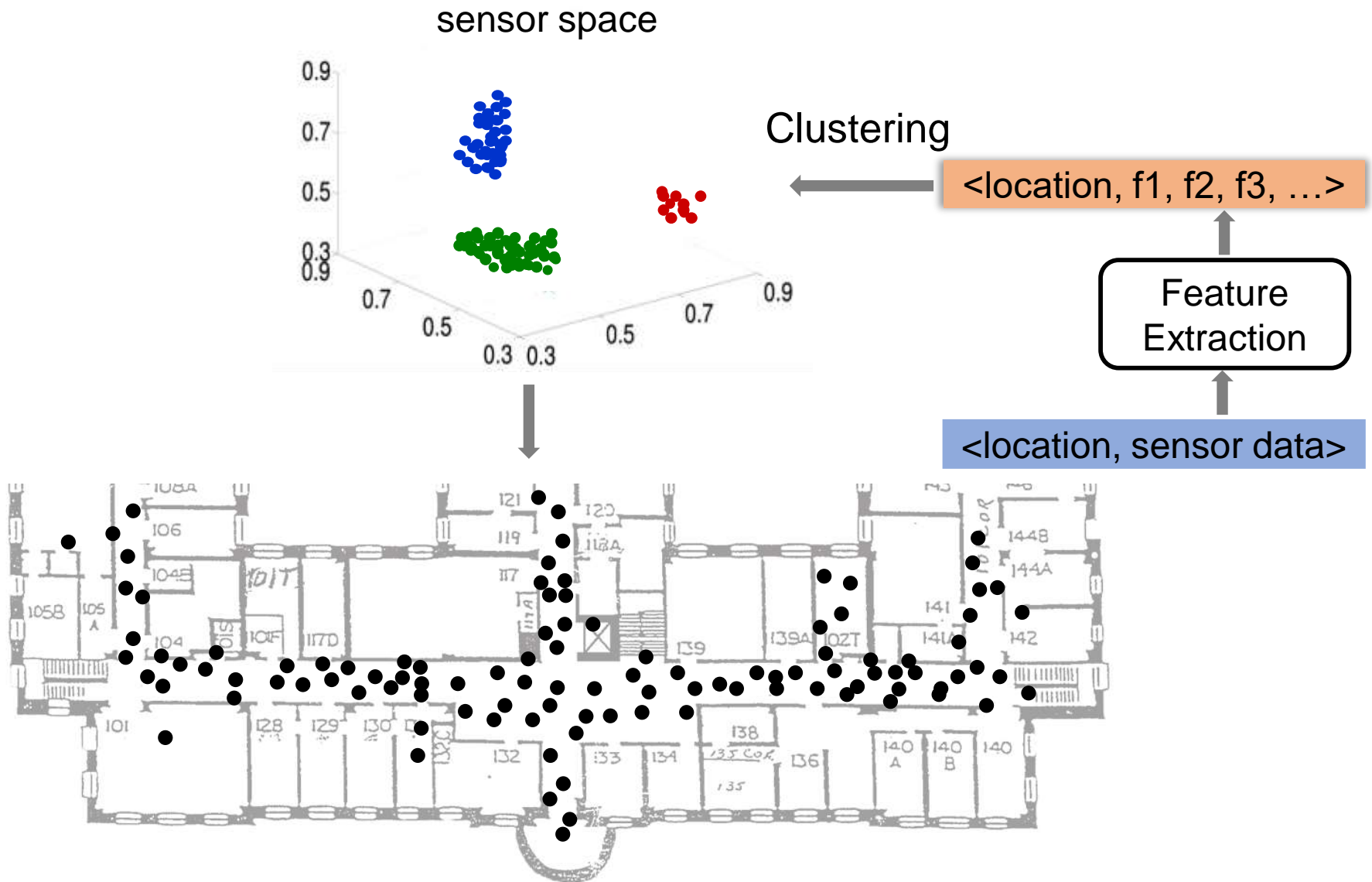
<location, f1, f2, f3, ...>

Feature Extraction

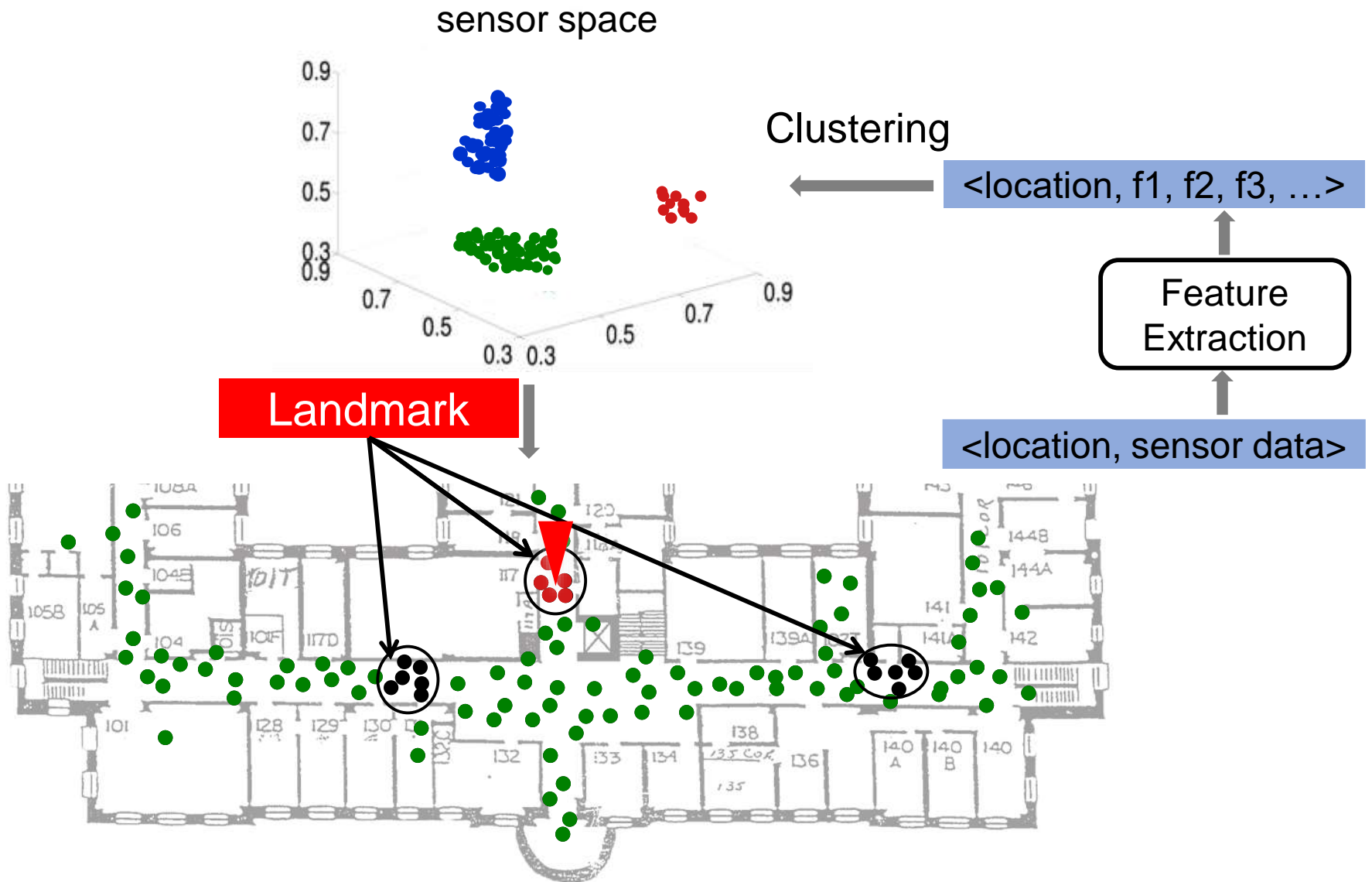
<location, sensor data>



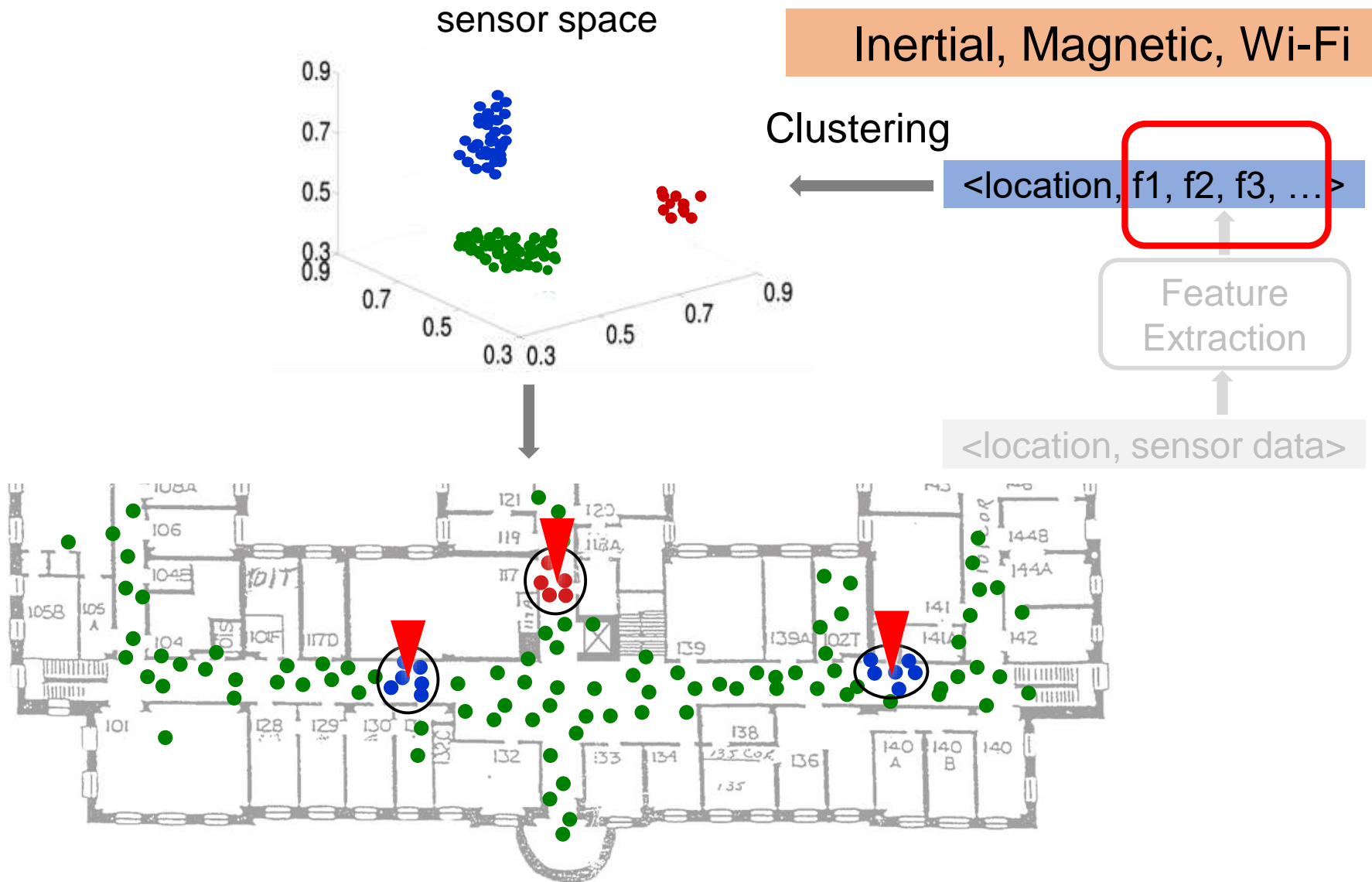
Raw Sensor → Landmarks



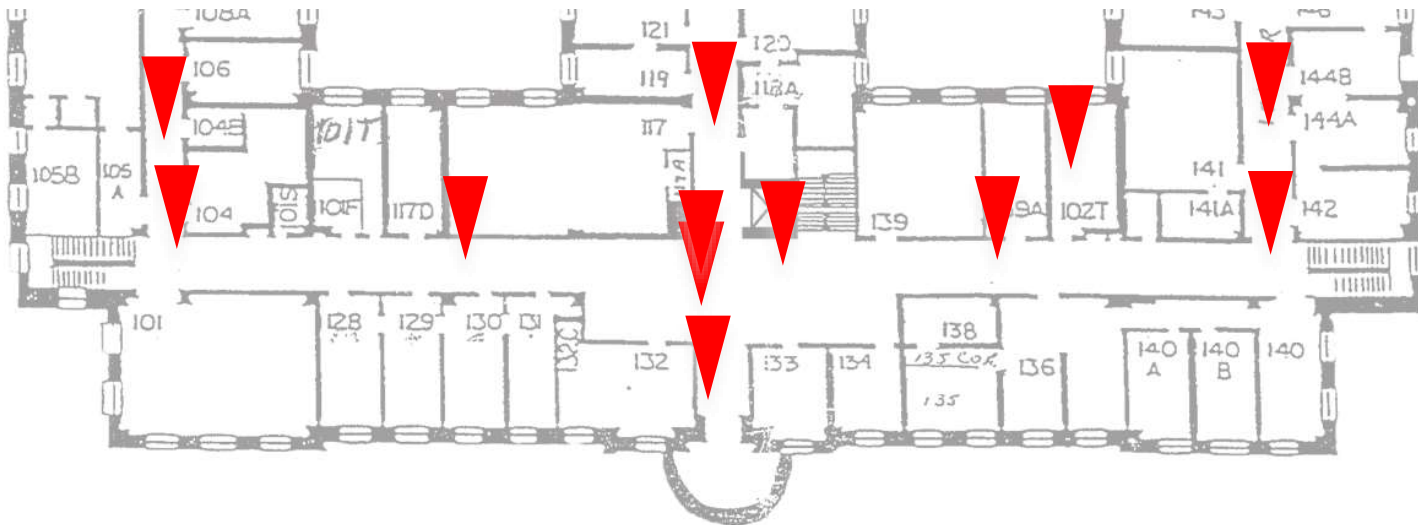
Raw Sensor → Landmarks



Landmarks from Multiple Sensors

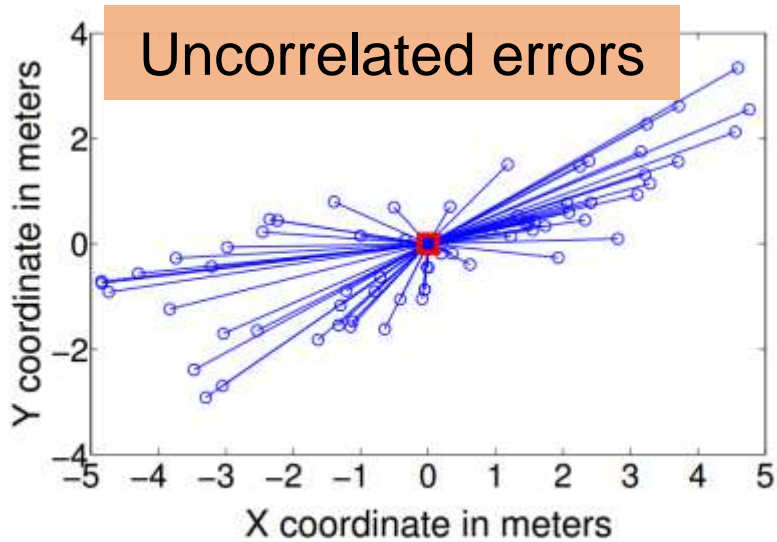
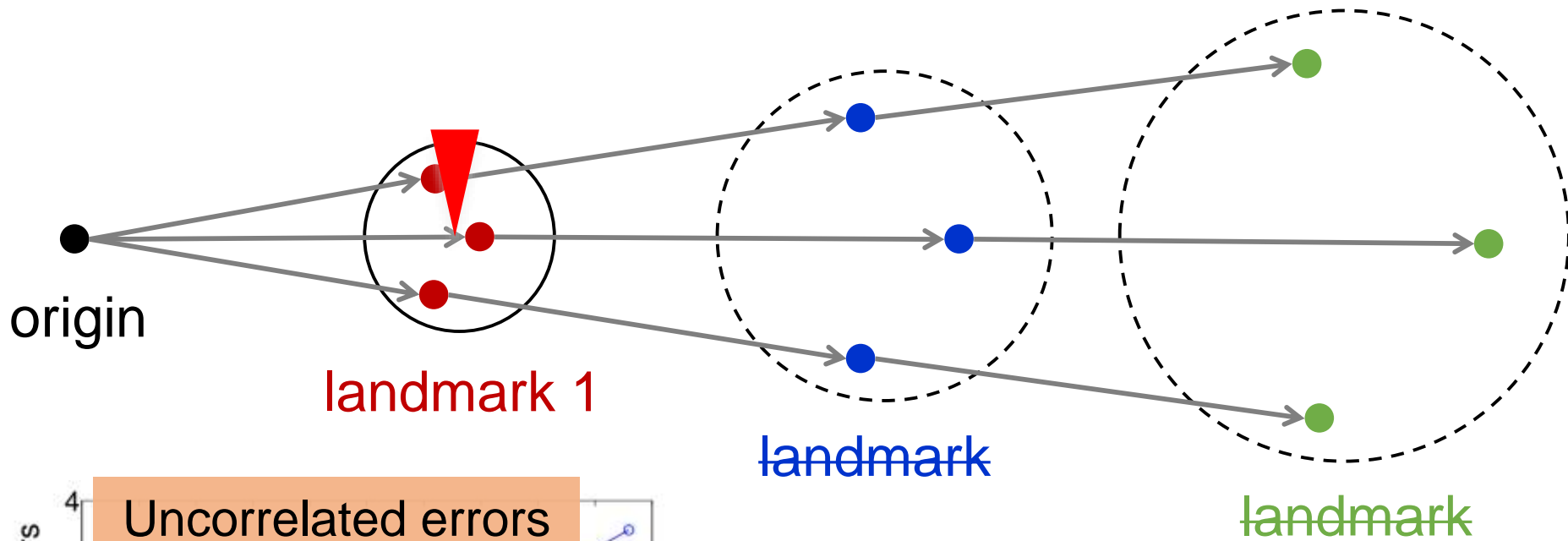


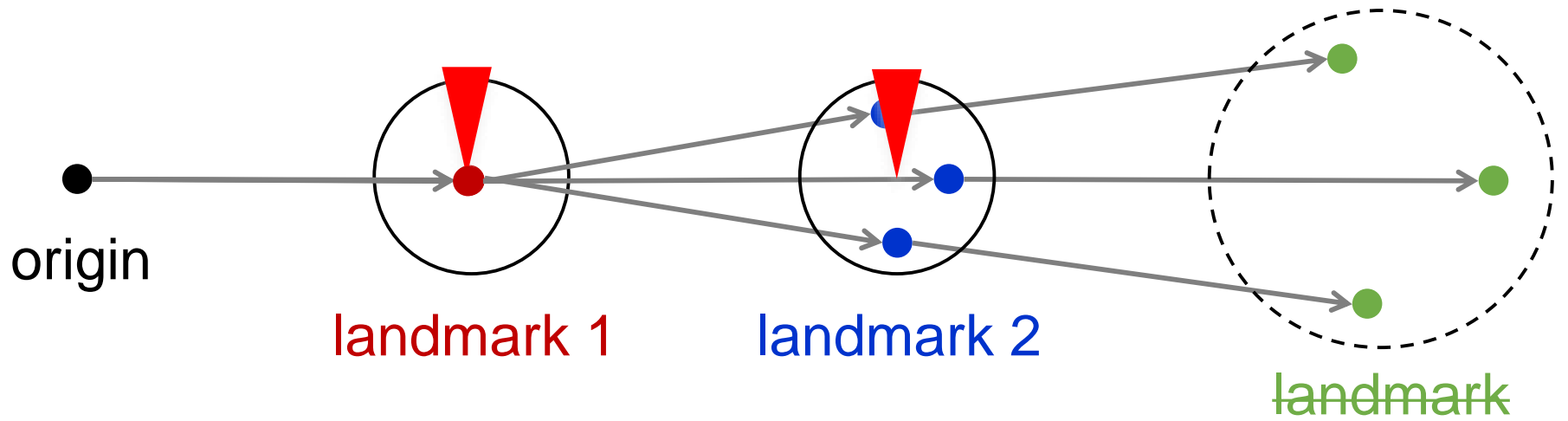
Say we find many landmarks (using multiple sensors).
Are we done?

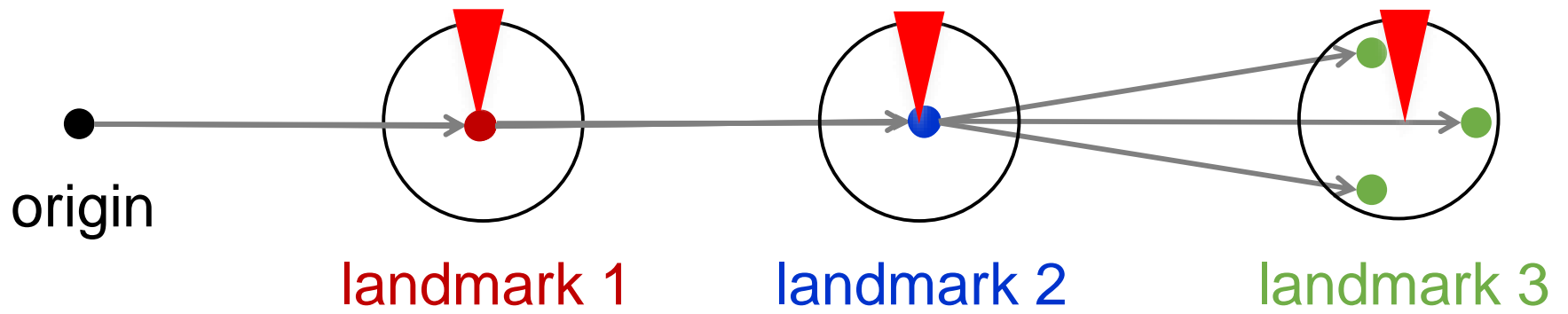


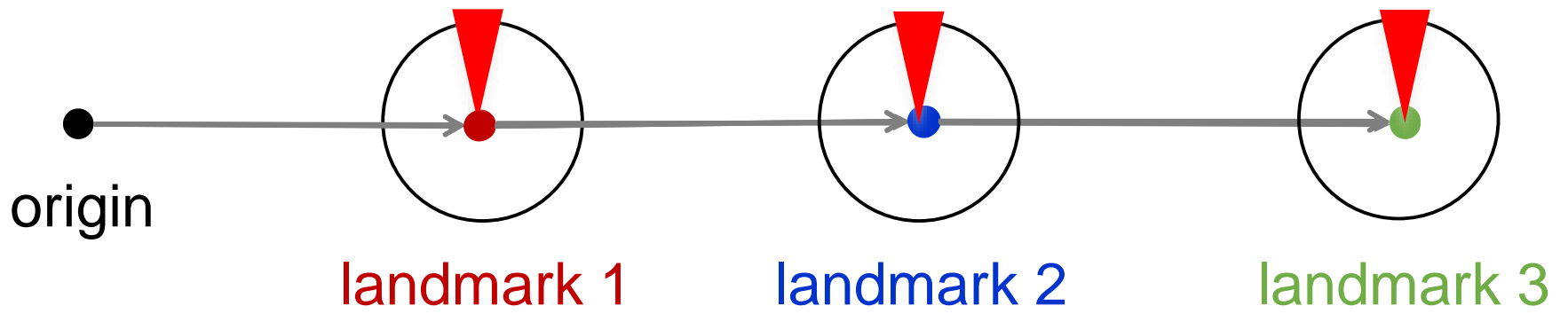
Say we find many landmarks (using multiple sensors).
Are we done?

No, landmark locations can be very poor.

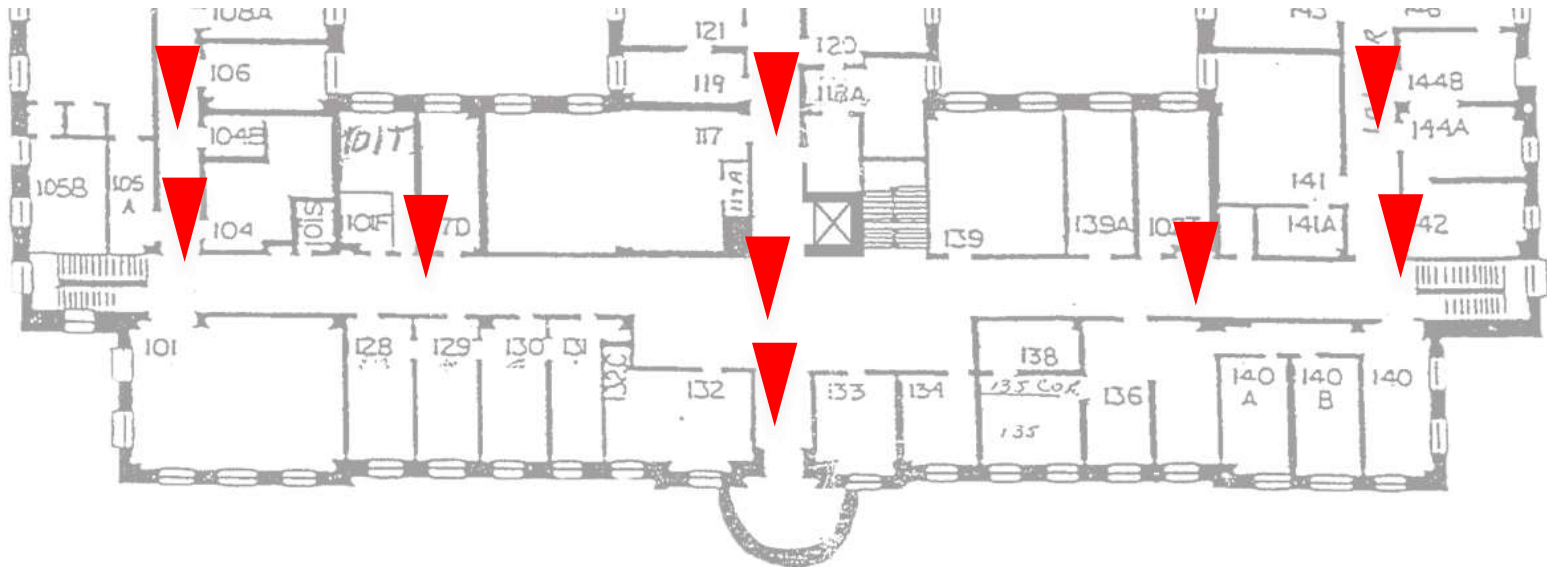




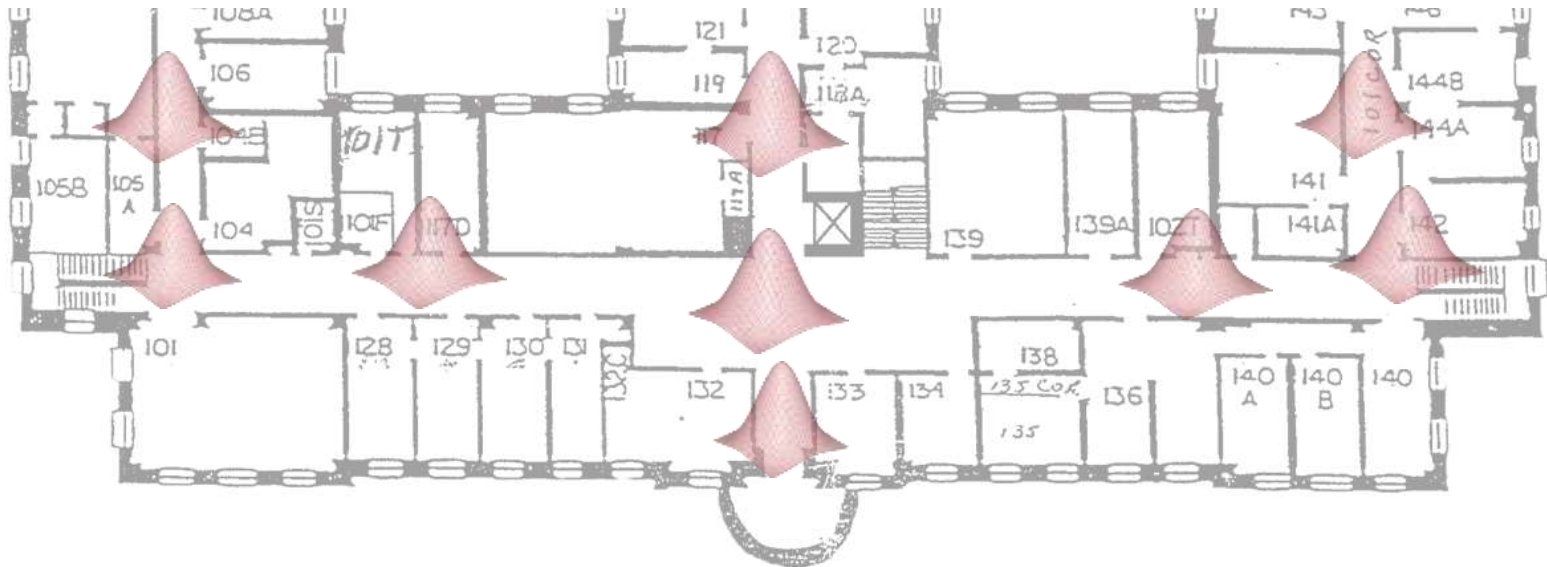




Growing landmarks outward from initial location



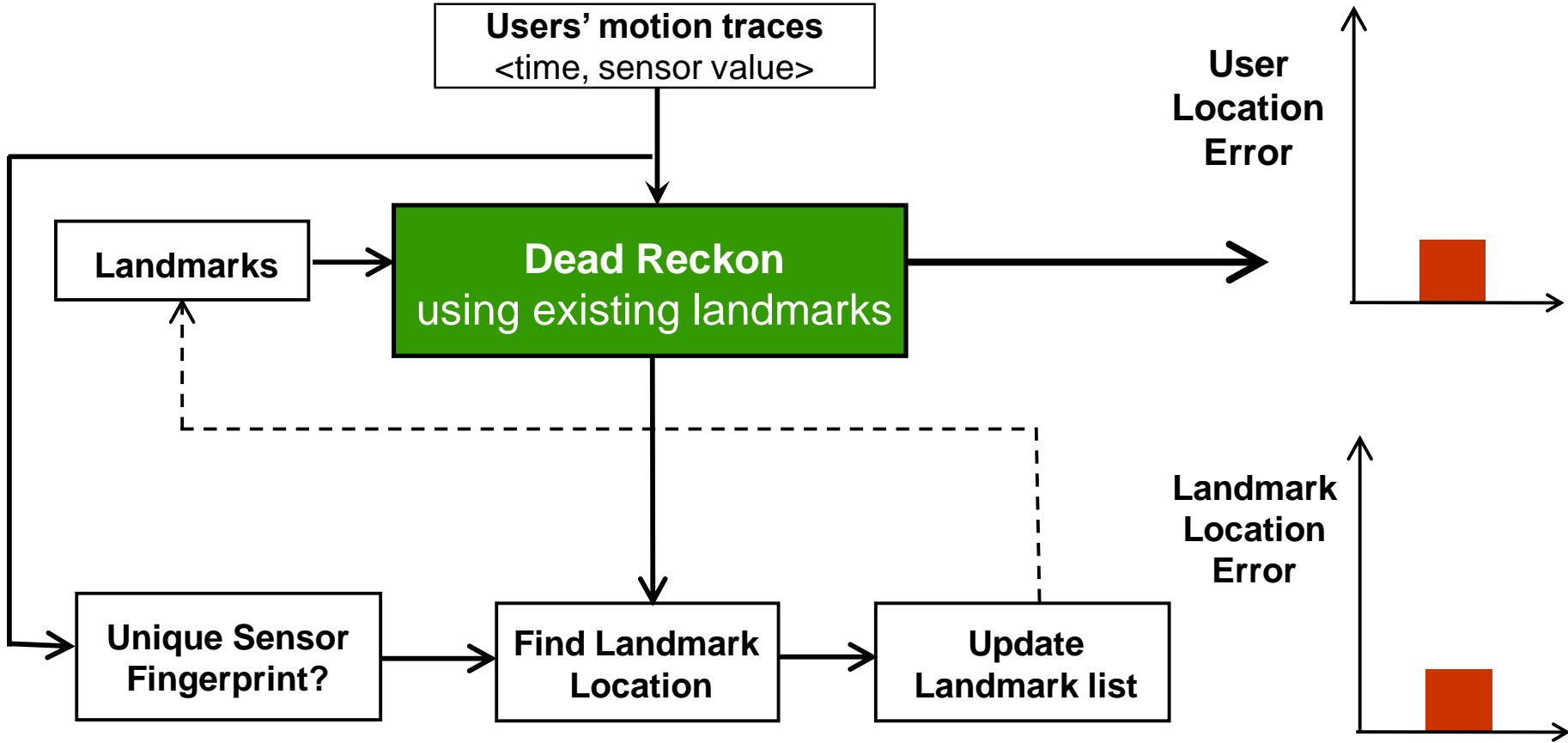
Growing landmarks outward from initial location



Recursive Algorithm



Users' motion traces
<time, sensor value>



UnLoc Demo



SCIENTIFIC
AMERICAN™

WIRED

THE VERGE

FAST COMPANY...

UnLoc Building: CSL Floor: 2 Trace #: 1

load load replay show sensors calculate landmarks show panel

Legend

- Inertial
- Magnetic
- Wi-Fi

clear

trace display: trace marker



SCIENTIFIC AMERICAN™

WIRED

THE VERGE

FAST COMPANY...

Questions?

Evaluation:

- Deployed in 6+ buildings
- Shopping mall, univ., industry
- Results from 5 Android models
- 20 users

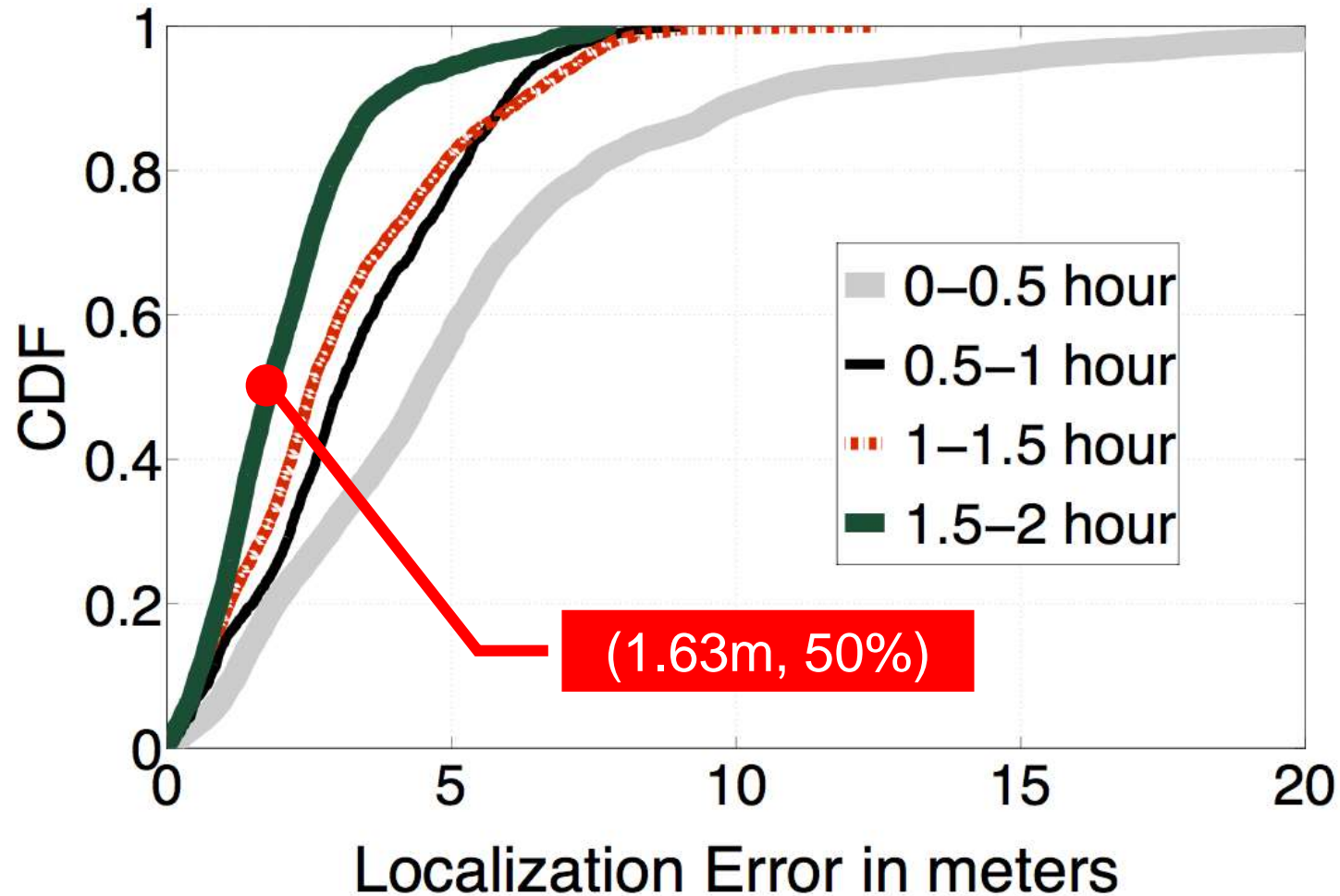
- Running live in CSL 2nd floor
- Landmarks 6 months stale
- Robust



Performance

Experimentation on 8000 sq. meters

Shopping mall, ECE and CS buildings





Indoor environments rich in landmarks



1.63m accuracy

No infrastructure cost

No calibration needed