Spectrum Sensing Over Multipath Fading Channels through Ofdm Signals for Cognitive Radios

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ABSTRACT:

This paper focuses on the matter of distributed composite hypothesis testing in a network of sparsely interconnected agents, during which only a little section of the field modeling parametric alternatives is noticeable at every agent. A recursive generalized likelihood ratio test (GLRT) type algorithm in a very distributed setup of the consensus-plus-innovations form is proposed, during which the agents update their parameter estimates and decision statistics by at the same time processing the newest sensed information (innovations) and information obtained from neighboring agents (consensus). This paper characterizes the conditions and also the testing algorithm design parameters that make sure that the chances of decision errors decay to zero asymptotically within the giant sample limit. Finally, simulations studies are presented that illustrate the findings.

Index Terms—Distributed Inference, Consensus Algorithms, Generalized Likelihood Ratio Tests, Hypothesis Test-ing, Large Deviations Analysis.

I.INTRODUCTION

This paper revolves around testing a straightforward hypothesis against a composite alternative in a distributed multi-agent network. The hypotheses form a parametric family indexed by a (finite-dimensional vector) signal parameter, during which the null hypothesis corresponds to absence of signal, whereas, the collection of non-zero parameter values correspond to the (continuous) composite alternative. broadly speaking, the objective is to simultaneously estimate the underlying parameter or state of the environment and decide that hypothesis is true based on the time-sequentially collected measuring data at the agents. This drawback captures several sensible applications together with cooperative spectrum sensing [1] and MIMO radars [2]. The Generalized likelihood ratio Tests (GLRT) ([3]) algorithm could be a classical approach that has been used wide in centralized setups for addressing such issues of composite testing. Except for being inherently centralized, the GLRT relies on batch processing of observation data; additional, due to the waiting time concerned in obtaining a reasonably smart estimate of the underlying parameter so as to ensure reasonable detection performance subsequently, its implement ability in real-time applications could also be restricted. Moreover, the estimation and detection schemes running serially rather than during a parallel fashion con-sume plenty of sensing energy which cannot go well with most multi-agent network situations that are generally energy constrained. Motivated by such constraints, we tend to propose an algorithm CIGLRT, a totally distributed recursive testing procedure, during which agents coordinate through local peer-to-peer info exchange and, specially, the detection and estimation schemes run in parallel. Before elaborating additional on the setup and therefore the proposed distributed approach, we briefly review related existing work on distributed hypothesis testing in collaborative multi-agent networks. Distributed detection schemes as studied within the literature is broadly classified into 3 categories. Fusion center based mostly architectures, wherever all the relevant info is transmitted to the fusion center by the agents and therefore the subsequent inference schemes are operated by the fusion center (see, as an example [4, 5]), constitutes the primary category. accord schemes, that are distributed setups, wherever {the data the info the info} collection phase by the agents is followed by information exchange among them to achieve a choice (see, as an example [6, 7]) represent the second category, whereas the third category consists of schemes that perform simultaneous assimilation of data obtained from sensing and communication during a recursive time sequential manner (for example [8, 9]). The algorithm we tend to present during this paper belongs to the third category, wherever agents build conditionally independent and temporally identically distributed (but probably spatially heterogeneous) observations and update their parameter estimate and test statistic by simultaneous assimilation of {the info the knowledge the data} obtained from the neighboring agents (consensus) and therefore the latest locally detected information (innovation). This justifies the name CIGLRT which may be a distributed GLRT kind algorithm of the consensus + innovations type. during this paper, thus on closely replicate typical practical sensing environments, we tend to assume Associate in Nursing agent's observations, say for agent n, is Mn dimensional, wherever Mn<< M, M being the dimension of the underlying static vector parameter. We tend to not only show the consistency of

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the parameter estimate sequence however conjointly show the existence of possible alternative of thresholds and alternative algorithmic program style parameters that make sure that the chances of errors decay to zero asymptotically.

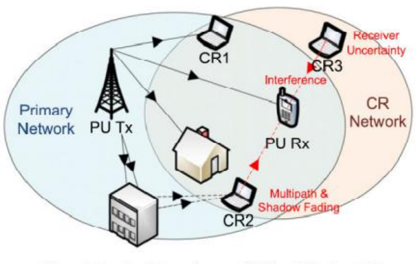

Fig: 1.basic diagram of cognitive radio network.

estimate sequence however conjointly show the existence of possible alternative of thresholds and alternative algorithmic program style parameters that make sure that the chances of errors decay to zero asymptotically. (Fully) distributed detection schemes, in literature until currently square measure involved with either binary straightforward hypothesis testing (see, for instance [8–10]) or multiple straightforward hypothesis testing (finite classification) (see, for ex-ample [11–13]) in distinction with the composite hypotheses with constant vector parameterization as studied during this paper. what is more, in [11–13] the observability condition assumed needs a minimum of one agent to be able to distinguish between each attainable try of parameters, whereas, we have a tendency to need the weakest kind of observability, i.e., the mixture observation model is evident for the parameter of interest, brought up as world observability therefore forth. the world observability demand is important, even for a centralized procedure having access to any or all agent knowledge in any respect times, for attaining consistent parameter estimates within the massive sample limit. Addressing the totally composite testing setup with a nonstop vary of alternatives needs novel technical machinery within the kind of development of study of economical distributed estimation and detection procedures that act in an exceedingly closed-loop system fashion that we have a tendency to pursue during this paper. The remainder of the paper is organized as follows. Spectral graph theory, preliminaries and notation square measure mentioned next. The sensing model is delineate in Section two, wherever we have a tendency to conjointly review some preliminaries regarding the classical Generalized probability Ratio Tests. Section 3 presents the proposed CIGLRT algorithm, while Section 4 concerns with the main results of the paper. The simulation results are stated in Section 5. Finally, Section 6 concludes the paper.

Spectral Graph Theory:

The inter-agent communication network is a simple[1] undirected graph $G = (V, E)$, where V denotes the set of agents or vertices with cardinality $|V| = N$, and E the set of edges with $|E| = M$. If there exists an edge between agents i and j, then $(i,j) \in E$. A path between agents i and j of length m is a sequence $(i = p_0, p_1, \ldots, p_m = j)$ of vertices, such that $(p_t, p_{t+1}) \in E$, $0 \leq t \leq m-1$. A graph is connected if there exists a path between all possible agent pairs. The neighborhood of an agent n is given by $\Omega_n = \{j \in V \mid (n,j) \in E\}$. The degree of agent n is given by $d_n = |\Omega_n|$. The structure of the graph is represented by the symmetric NxN adjacency matrix $A = [A_{ij}]$, where $A_{ij} = 1$ if $(i,j) \in E$, and 0 otherwise. The degree matrix is given by the diagonal matrix $D = diag(d_1 d_N)$. The graph Laplacian matrix is defined as $L = D-A$. The Laplacian is a positive semi definite matrix, hence its eigenvalues can be ordered and represented as $0 = \lambda_1(L) \leq \lambda_2(L) \leq \ldots \lambda_N(L)$. Furthermore, a graph is connected if and only if $\lambda_2(L) > 0$ (see [14] for instance).

2. FADING:

In wireless communications, fading is variation of the attenuation of a signal with varied variables. These variables embrace time, geographical position, and radio frequency. Fading is usually modeled as a random process. A fading channel could be a communication channel that experiences fading. In wireless systems, fading could either be due to multipath propagation, referred to as multipath induced fading, weather (particularly rain), or shadowing from obstacles affecting the wave propagation, sometimes referred to as shadow fading.

2. SENSING MODEL AND PRELIMINARIES

There are N agents deployed in the network. Every agent n at time index t makes a noisy observation $y_n(t)$, a noisy function of which is a deterministic but unknown parameter and 2 U R^M , where U is an open set in R^M . Formally the observation model for the n^{th} agent is given by

$$\mathbf{y}_n(t) = \mathbf{H}_n \theta^* + \gamma_n(t),$$

Where $\{y_n(t)\} \in R^{Mn}$ is the observation sequence for the n^{th} agent and $\{\gamma(t)\}$ is a zero mean temporally i.i.d Gaussians noise sequence at the n^{th} agent with nonsingular co-variance $\sum_n$, where $\sum_n \in R^{MnMn}$. Furthermore, the noise processes at 2 totally different agents n; l for n-6= l are independent. motivated by most practical networked-agent applications, every agent solely observes a subset of the elements of , such Mn<< M. under such a condition, in isolation, an agent will solely estimate a region of the parameter, because the native sensing functions Hn's are not one-to-one on U. but

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under appropriate network observability conditions and through inter-agent collaboration, it would be possible for every agent to get a consistent estimate of . Moreover, de-pending on that hypothesis is in effect, the observation model is formalized as follows:

$$\mathcal{H}_1 : \mathbf{y}_n(t) = \mathbf{H}_n\theta^* + \gamma_n(t)$$
$$\mathcal{H}_0 : \mathbf{y}_n(t) = \gamma_n(t).$$

We formalize the assumptions on the inter-agent communication graph and global observability. Assumption B1. We require the following global observability condition. The matrix G $= \Sigma_{n=1} H_n\ \Sigma_n H_n$ is full rank. Assumption B2. The inter-agent communication graph, modeling the information exchange among the agents, is connected, i.e. $_2$(L) > 0, where L denotes the associated graph Laplacian matrix. In order to motivate our distributed testing approach (presented in Section 3), we now review some concepts from Generalized Likelihood Ratio Testing. In a generalized target detection problem, let the absence of target be modeled by a simple hypothesis H_0, whereas, its presence corresponds to a composite alternative H_1 as the underlying parameter is unknown and can possibly attain a lot of values. Let y(t) = $y_1(t)^{>} y_N\ (t)^{>>}$represent the information from all the set up, during which the fusion center has access to any or all the agents' observations i.e. y(t) in any respect times t, a classical testing approach is that the generalized likelihood ratio test (GLRT). Formally, the GLRT decision rule is defined wherever could be a predefined threshold and which represent the likelihood of observant y under H0 and H1 respectively. Now, with the idea that the observations made by the agents are not absolutely independent, we have, The computation of the decision statistic within the maximization in (5) that uses all the information collected so far, is that the key bottleneck within the implementation of the classical GLRT. In general, a maximize of (5) is not known apriori because it depends on the raw data instance, and hence as far as communication complexity within the GLRT implementation is concerned, the maximization step incurs the most important overhead indeed, a direct implementation of the maximization(5) needs access to the whole data y at the fusion center. To mitigate the communication complexity in realizing a fusion center having access to all or any the information, we have a tendency to present a distributed algorithm within which agents collaborate locally to get a maximizing nine. so as to get reasonable decision performance with such localized communication, we have a tendency to propose a distributed detector of the consensus + innovations type, that are introduced in [15, 16]. especially, every agent sequentially updates its parameter estimate and decision statistic in 2 parallelly running recursive schemes by assimilating info obtained from its neighbors (consensus potential) and latest detected local information (innovation potential).In this section, we have a tendency to develop the algorithm CIGLRT for linear observation models. In Section four we have a tendency to state the most results regarding the characterization of the thresholds that guarantee asymptotically decaying possibilities of errors. We have a tendency to skip the proofs attributable to space limitations. The proofs will be found within the longer manuscript ([17]).

Algorithm CIGLRT

The algorithm CIGLRT consists of two parts, namely, the parameter estimate update and the decision statistic update. Parameter Estimate Update. The algorithm CIGLRT generates the sequence f_n(t)g 2 RM at the n[th] agent according to the following recursive scheme where n denotes the communication neighborhood of agentn, f_tg and f_tg are consensus and innovation weight sequences respectively (to be specified shortly). The update in(6) can be written in a compact manner as follows:

We make the following assumptions on the weight sequences $\{\alpha_t\}$ and $\{\beta_t\}$.Assumption B3. The weight sequences $\{\alpha_t\}$ and $\{\beta_t\}$ are of the form $_t = (t+1)^1$; $_t = b\,(t+1)^2$, where b > 0 and0 < δ_2< 1/2.

Decision Statistic Update:

The algorithm CIGLRT generates the decision statistic sequence $\{z_n(t)\}$ at the n[th] agent according to the distributed recursive scheme

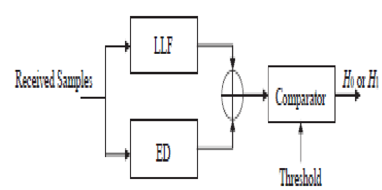

Fig. 2. Proposed detection scheme.

where fθ (.) and f_0(.) represent the likelihoods under H_1 and where G (t) = diag[$_1(t)^T H^{>}_1$; ; $_N (t)^T H^{>}_N$]. It is to be noted that the entries of the weight matrix W = I Lare designed in such a way that W is non-negative, symmetric, irreducible and stochastic, i.e., every row of W sums to one. Moreover, the second largest eigenvalue in magnitude of W, denoted by r, is strictly less than one (see [18]).Moreover, by the stochasticity of W, the quantity r satisfies

r = ||W - J||,

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$$H = H_0 \text{ if } z_n(t) \leq n,\ H = H_1 \text{ otherwise:} \qquad (10)$$

Under the aegis of such a decision rule, the associated probabilities of errors are as follows:

$P_{M1}\theta$ (t) = $P_1\theta(z_n(t) > n)$; $P_{FA}(t) = P_0(z_n(t) > n)$; (11)

where $P_{M;}$ and P_{FA} refer to probability of miss and probability of false alarm respectively and $P_{1,}\theta(.)$ and $P_0(:)$ denote the probability when conditioned on hypothesis H_1, which is in turn parameterized by θ, and the probability when conditioned on hypothesis H_0 respectively.

CIGLRT: MAIN RESULTS

In this section, we specifically characterize the thresholds for which the probability of miss and probability of false alarm decay to zero asymptotically. We also derive the large deviations exponent for the probability of false alarm.

D $\forall$ n, where $\Longrightarrow$ denotes convergence in distribution (weak convergence).

Theorem 4.1 asserts the asymptotic normality of the test statistic fz_n(t)g, 8n which in turn follows from the strong consistency of the parameter estimate sequence f $_n$(t)g which was studied in [19]. The next result concerns with the characterization of thresholds which ensures the probability of miss and probability of false alarm as defined in (11) decay to zero asymptotically.

Proposed scheme:

However, the optimum spectrum sensing over multipath fading channels remains an vital and challenging issue. Therefore, this work proposes an optimum Neyman-Pearson (NP) detector for spectrum sensing using CP. To observe the OFDM signal of primary users (PUs), the log- likelihood ratio (LR) test is developed by using the correlation characteristics of the redundancy of CP. Analytical results indicate that the LR of received samples is equivalent to their log likelihood function (LF) and LR of an energy detector (ED), subsequently permitting us to gain insights on the optimum NP detector. Since several unknown parameters want to be resolved, a practical generalized log likelihood ratio test (GLRT) is given. Moreover, to accomplish} a good performance over multipath fading channels, a channel independent GLRT (CI-GLRT) is used to derive an estimation of correlation coefficient independent of multipath channel profiles. Simulations confirm the benefits of the proposed detectors compared with state-of-the-art detectors

Evaluation results:

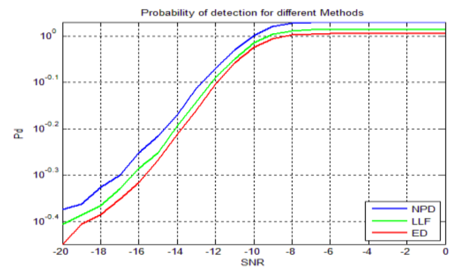

Fig. 1. Probability of detection plotted as a function of SNR for the NP Detector (16), the LLF detector (11), and the ED (14).

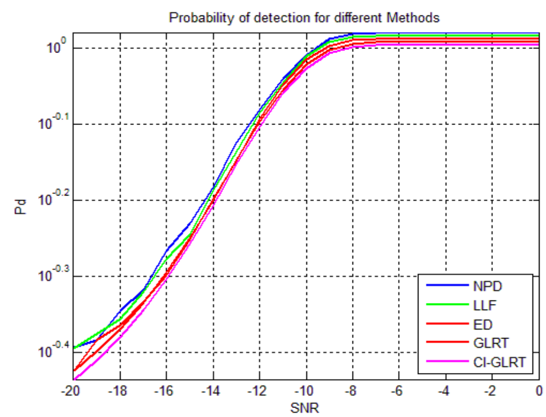

Fig. 2. Probability of detection plotted as a function of SNR for the NP detector, LLF detector, ED, GLRT detector, and CI-GLRT detector.

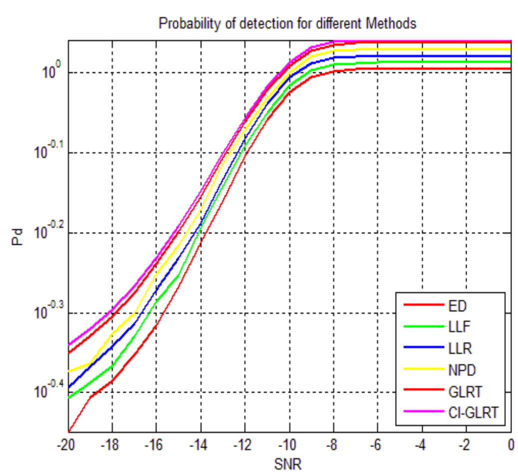

Fig. 3. Comparison of all CP-based detectors.

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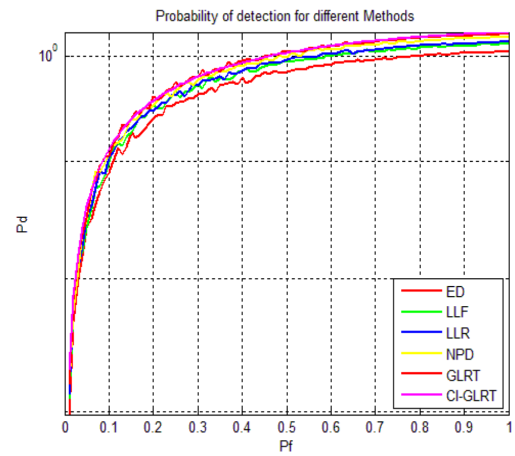

Fig. 4. Comparison of all CP-based detectors using the ROC. SNR= –9 db.

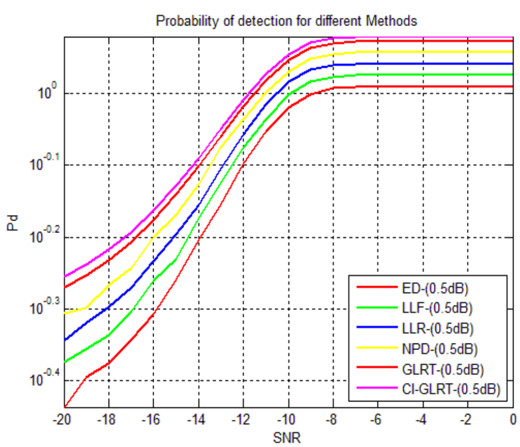

Fig. 5. Comparison between all CP-based GLRT detectors and ED. The influence of unknown parameters, 2*w*, with 0.5 dB uncertainty is Demonstrated.

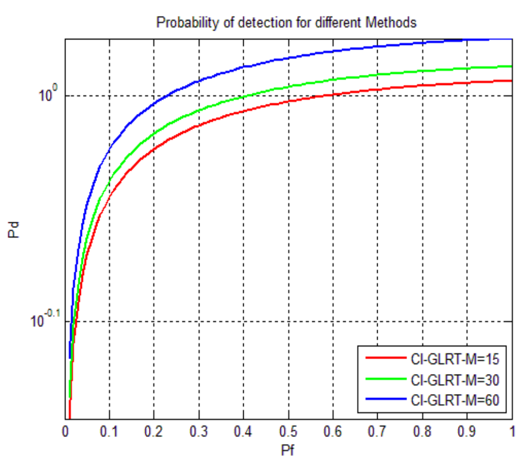

Fig. 6. ROC of the proposed CI-GLRT detector under the effects of *M* withNoise uncertainty of 0.5 dB SNR= –12 Db

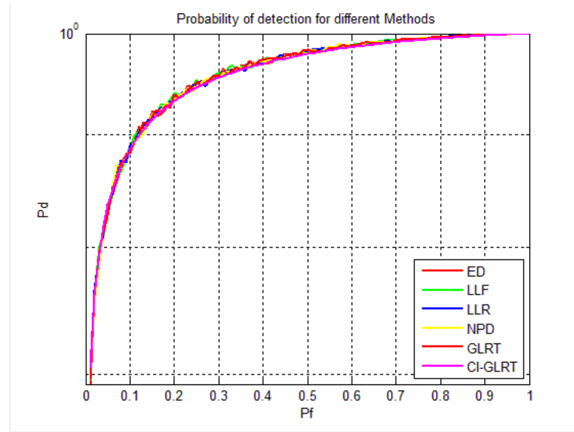

Fig:7 probability detection of optical detectors with 0:0.9 at the ration of log10

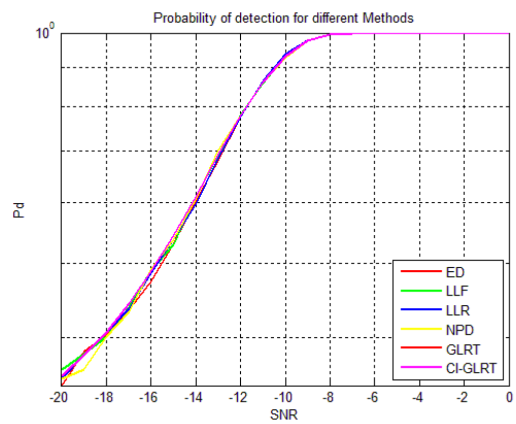

Fig 8:the SNR of the optical detector the ratio proceed with the high compatibility of 0:0.1:1 the consideration values are -10

CONCLUSION:

The optimum NP detector as well as practical implementations of this detector, particularly GLRT and CI-GLRT detectors, over general multipath fading channels was derived. The optimum detector was a combination of the LLF and LLR of the ED, that were determined to be asymptotically independent. The proposed NP detector will be used as a reference for designing alternative practical spectrum sensors applicable in numerous situations. This study indicated that substantial analysis is needed before spectrum sensing over multipath fading channels will be optimized. practical approaches for estimating numerous unknown parameters were proposed for use in the GLRT detector. The proposed CI-GLRT detector exhibited minor variation beneath the effects of channel PDPs and achieved the most favorable performance among all practical detectors; so, this detector is promising for application in spectrum sensing primarily based on cps.

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