Coverage and Adaptive Scheduling Algorithms for Criticality Management on Video Wireless Sensor Networks

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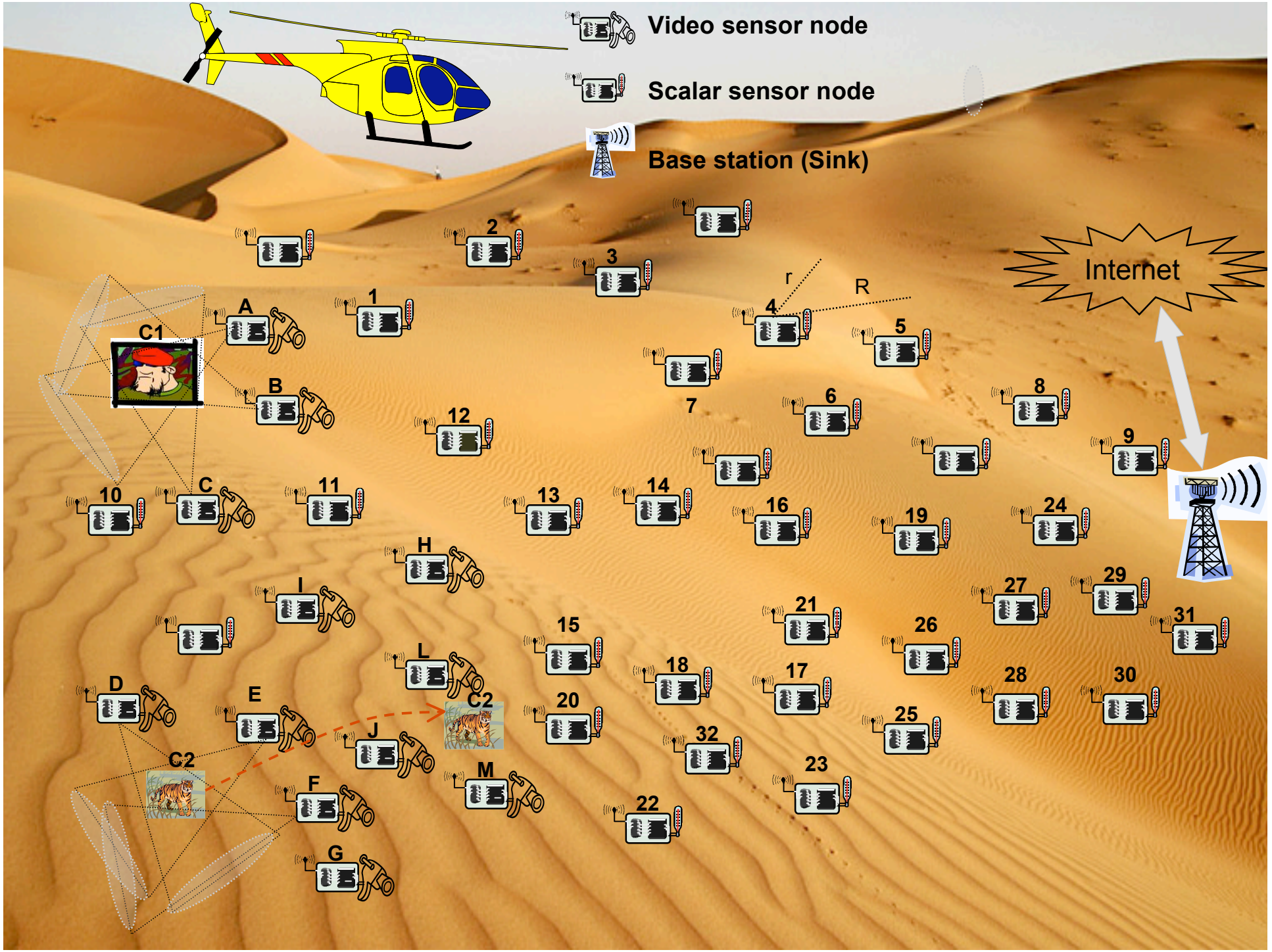
Overview

- Introduction of wireless video sensor networks
- Coverage and sensor scheduling problem
- Our scheduling algorithm for creating cover sets
- Adaptation to Application Criticality
- Experimental Results


Video sensor node
Scalar sensor node
Base station (Sink)
Internet
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R
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B
C
C1
C2
D
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J
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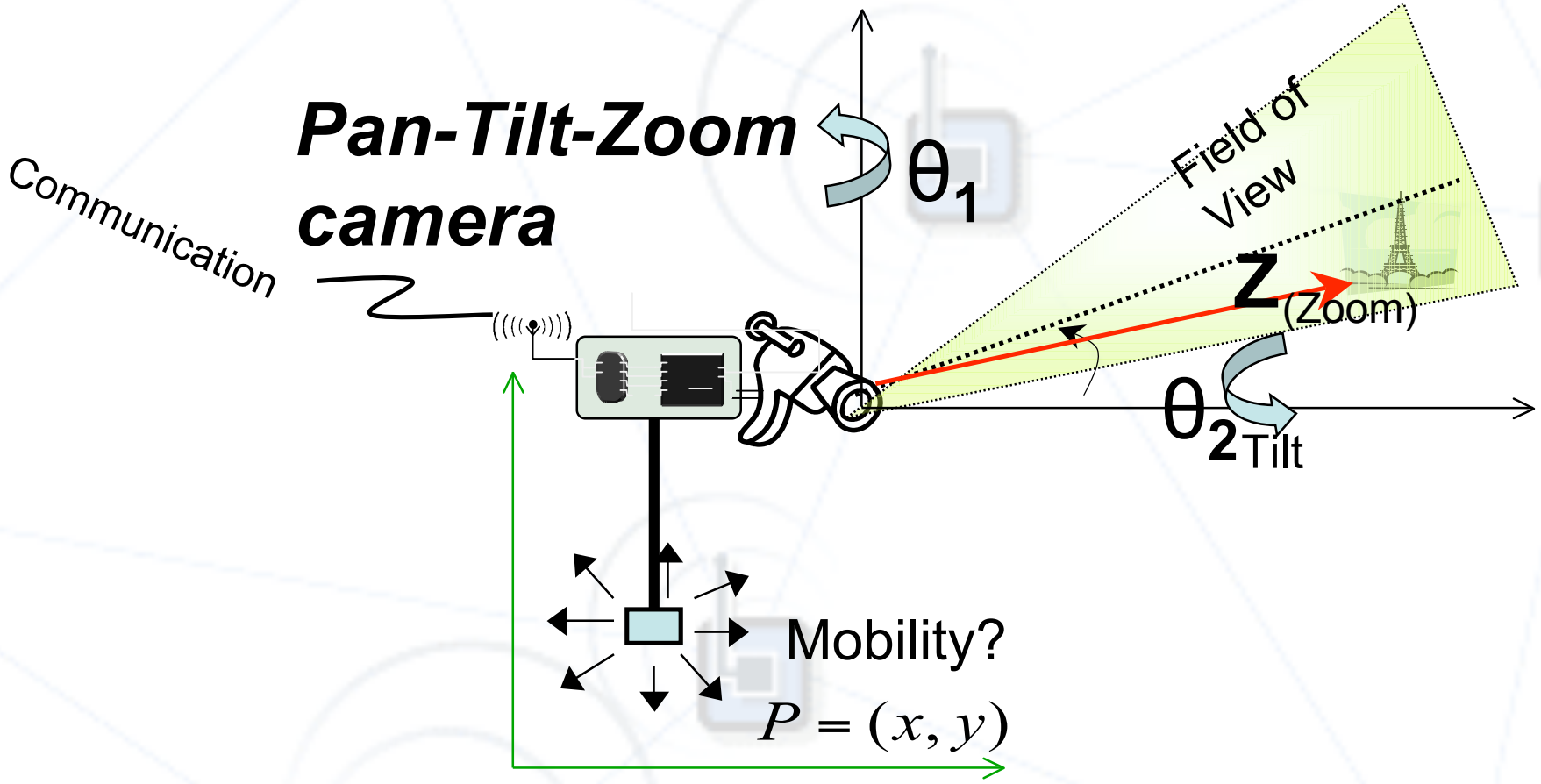
Video Sensor Node



$$N(P, \Theta_1, \Theta_2, Z)$$

Application's criticality

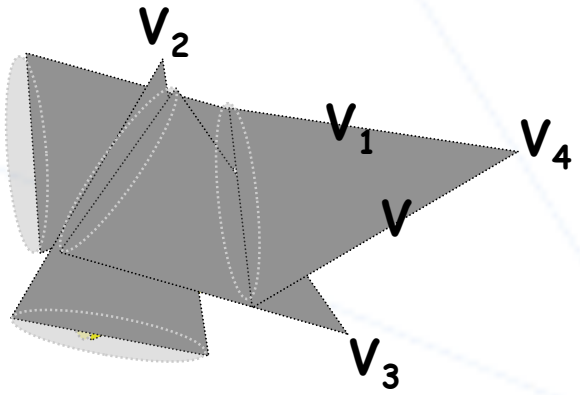
- All surveillance applications may not have the same criticality level, $r^0 \in [0,1]$
  - Environmental, security, healthcare,…
- Capture speed should decrease when r^0 decreases
- Sensor nodes could be initialized with a given r^0 prior to deployment

How to meet app's criticality

- Capture speed can be a « quality » parameter
- Capture speed for node v should depend on the app's criticality and on the level of redundancy for node v
- V's capture speed can increase when as V has more nodes covering its own FoV - cover set

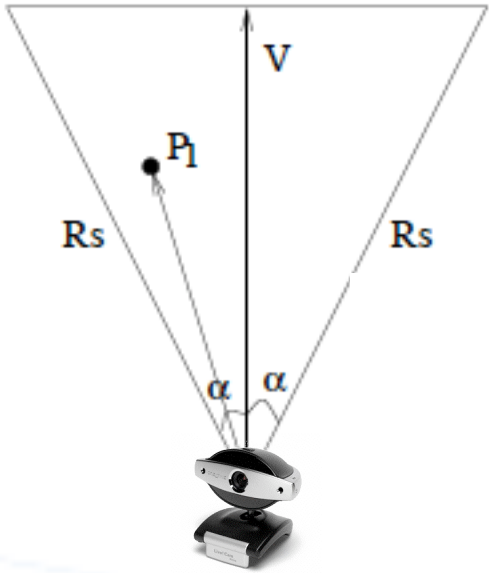
Node's cover set

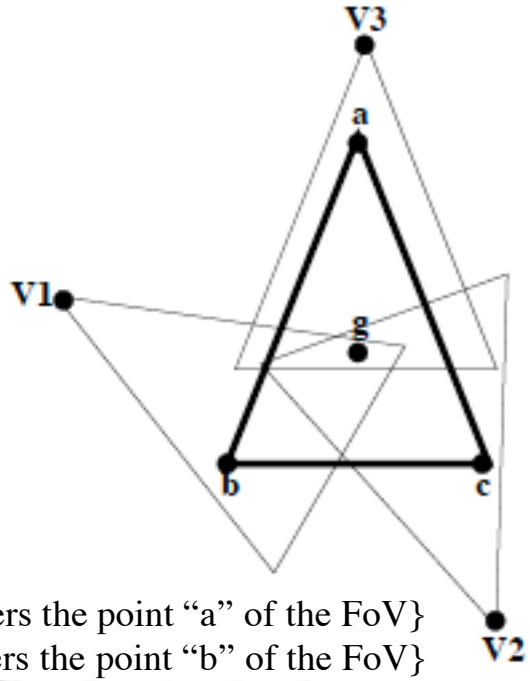
- Each node v has a Field of View, FoV_v
- $Co_i(v)$ = set of nodes v' such as $\bigcup_{v' \in Coi(v)} FoV_{v'}$ covers FoV_v
- Co(v)= set of $Co_i(v)$



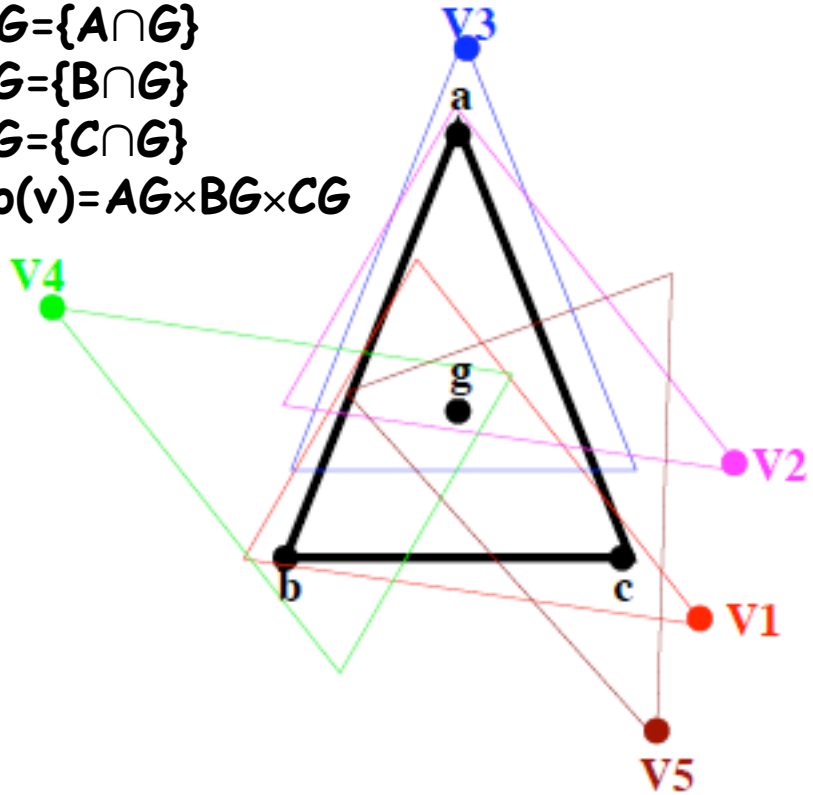
$$Co(v)=\{V_1, V_2, V_3, V_4\}$$

Finding v's cover set





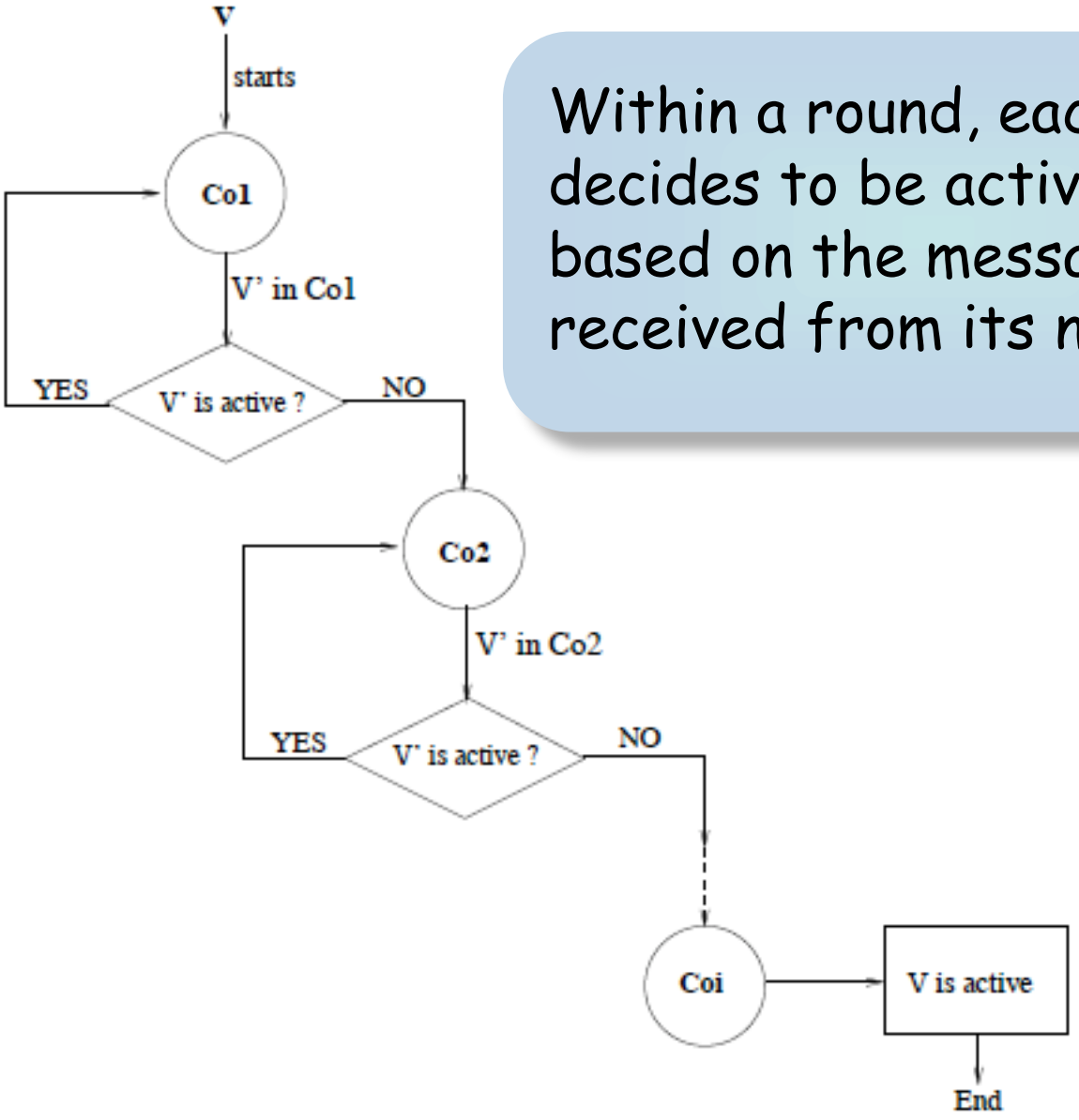
AG={A∩G}
BG={B∩G}
CG={C∩G}
Co(v)=AG×BG×CG



A = {v ∈ N(V) : v covers the point "a" of the FoV}
B = {v ∈ N(V) : v covers the point "b" of the FoV}
C = {v ∈ N(V) : v covers the point "c" of the FoV}
G = {v ∈ N(V) : v covers the point "g" of the FoV}

Co(V)= {
{V },
{V 2, V 1},
{V 3, V 1},
{V 2, V 4, V 5},
{V 3, V 4, V 5}}

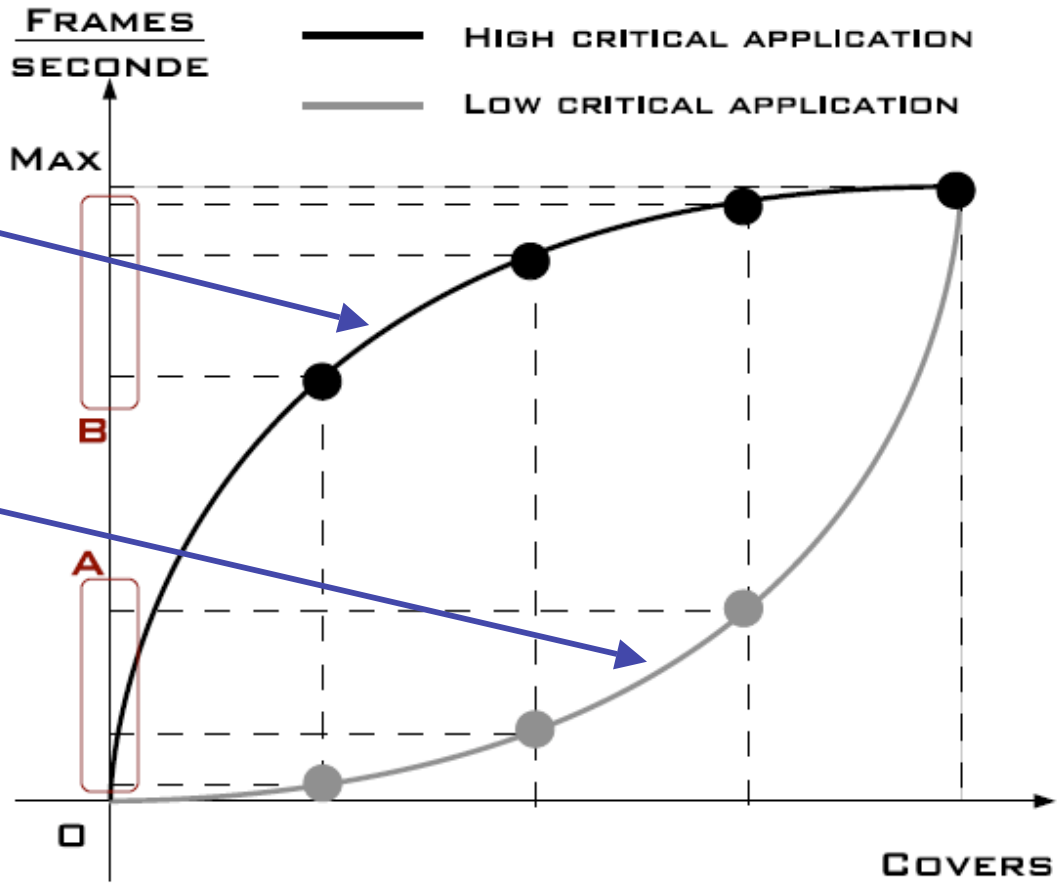
Active node selection



Within a round, each node decides to be active or not based on the messages received from its neighbors

Criticality model

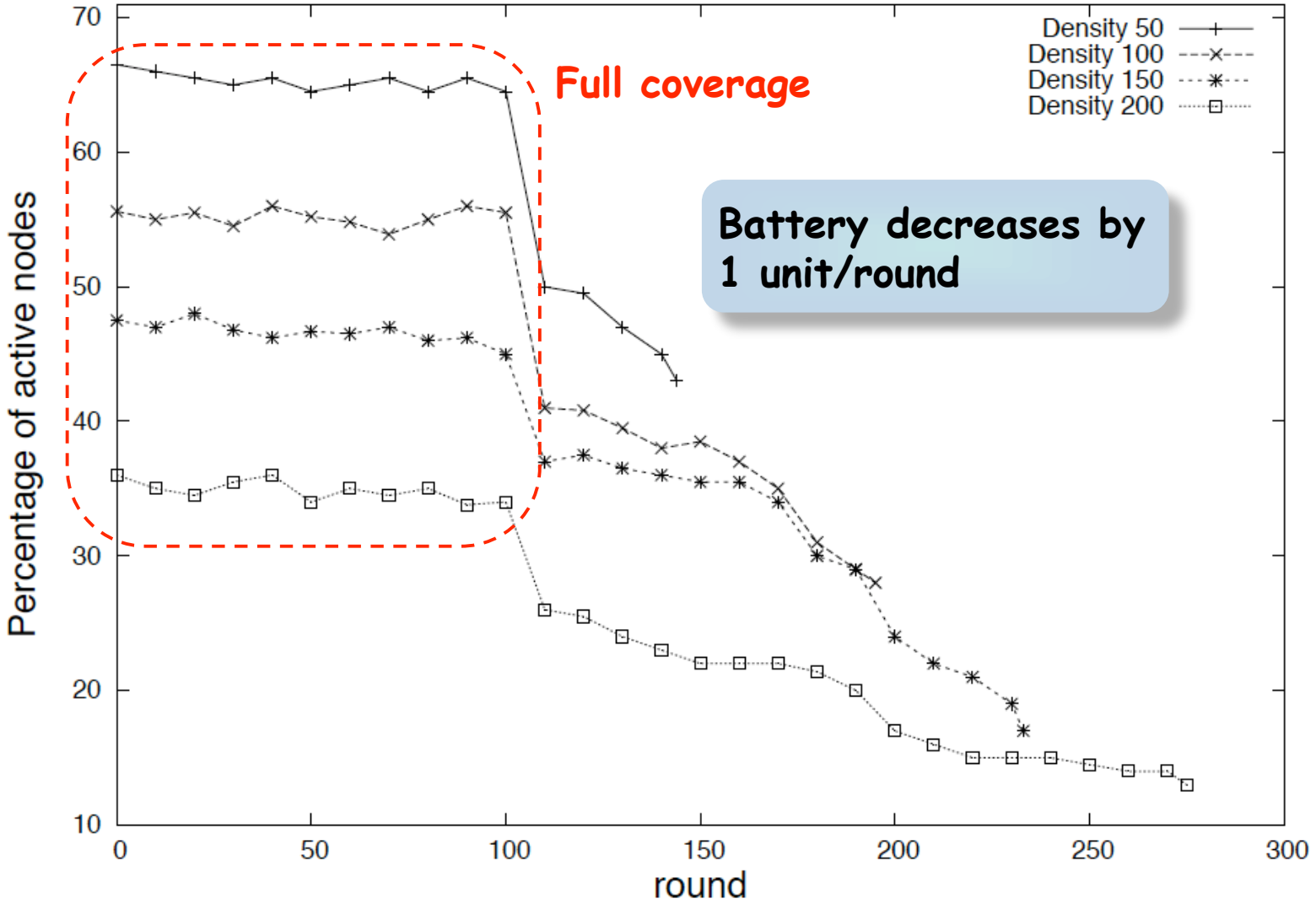
- Link the capture rate to the size of the cover set
- High criticality
  - Convex shape
  - Most projections of x are close to the max capture speed
- Low criticality
  - Concave shape
  - Most projections of x are close to the min capture speed
- Concave and convex shapes automatically define sentry nodes in the network



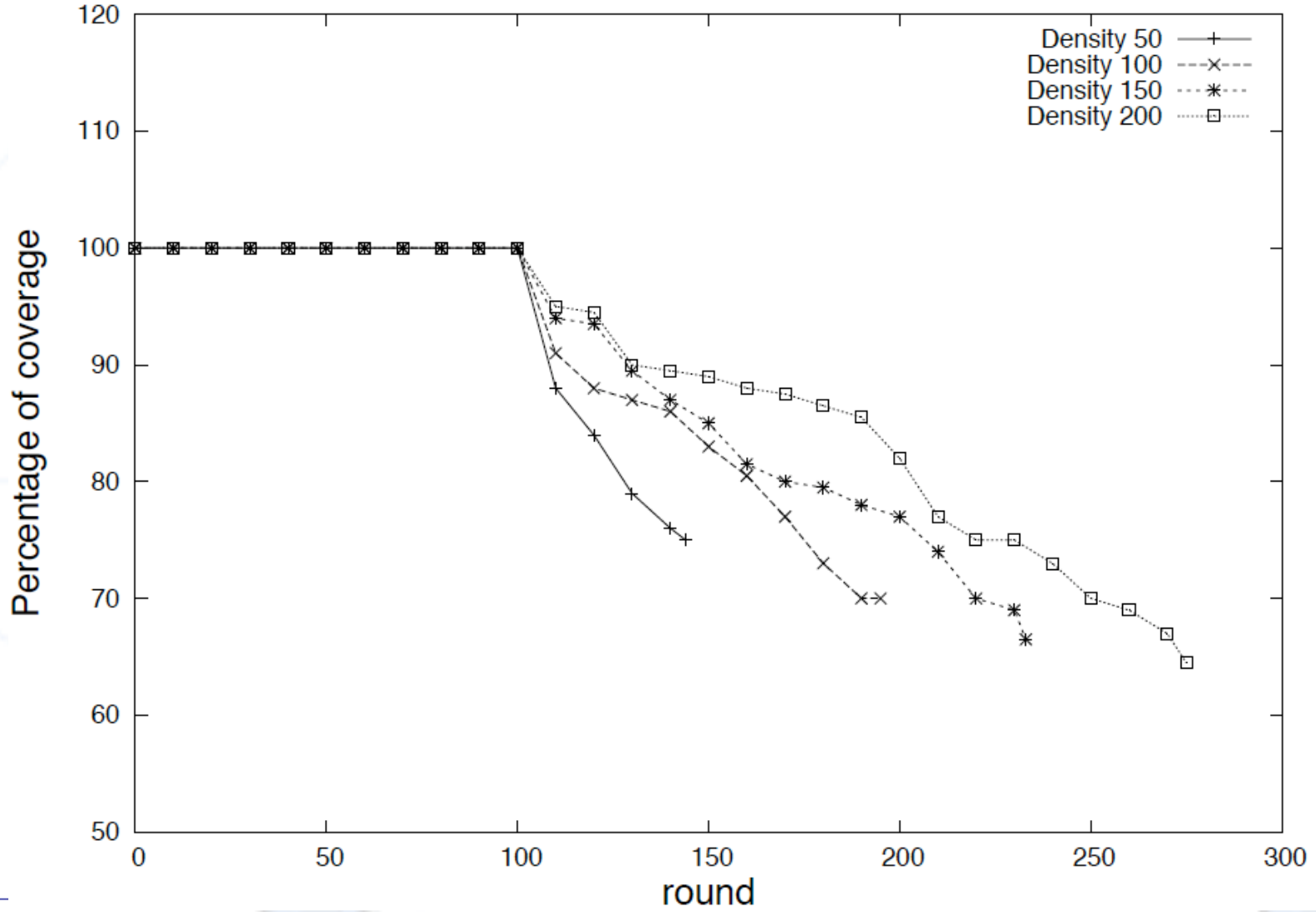
Simulation settings

- OMNET++ simulation model
- Video nodes have communication range of 30m and video sensing range of 25m, FoV is a sector of 60°
- Battery has 100 units
- Full coverage is defined as the region initially covered when all nodes are active

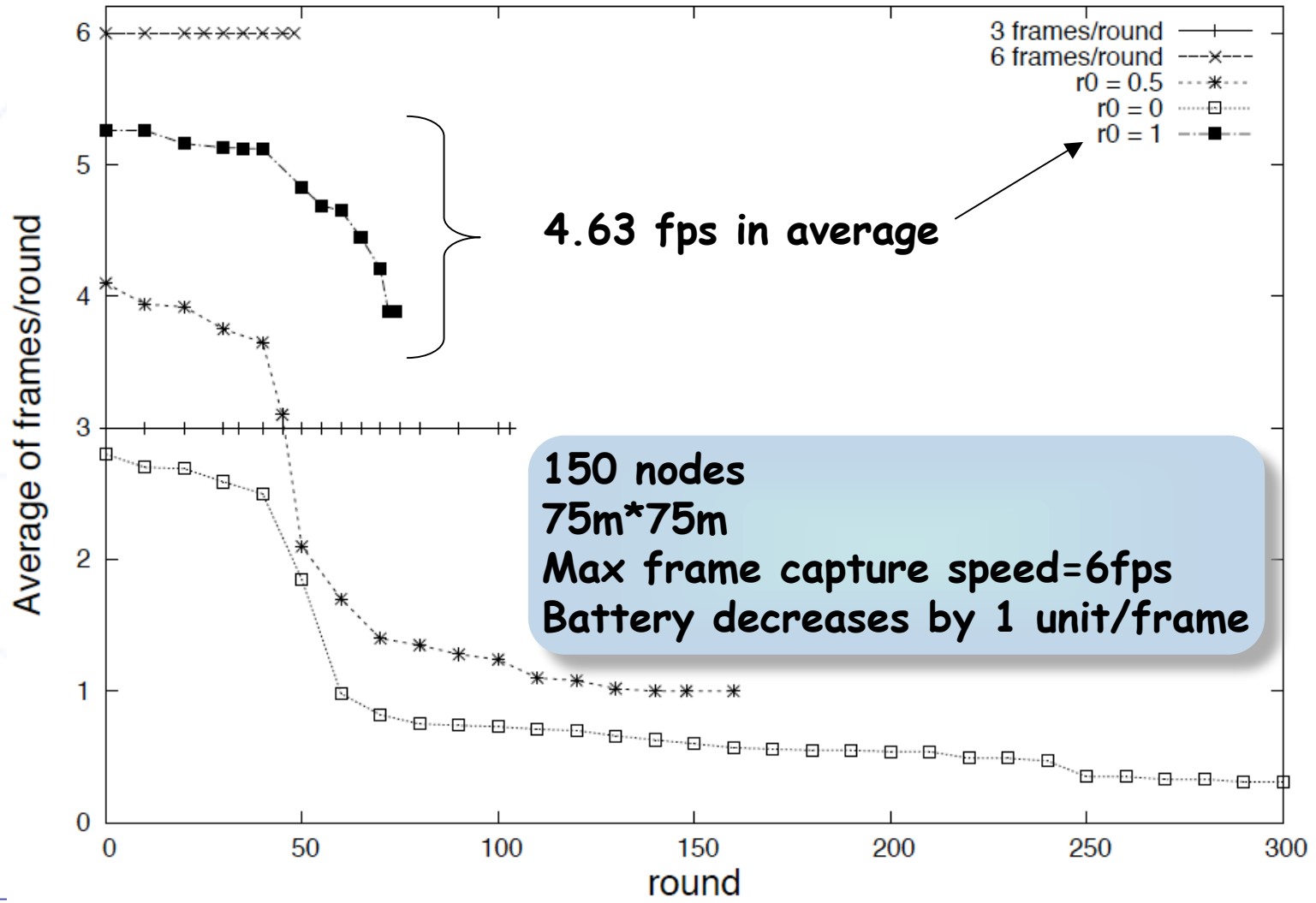
Percentage of active nodes



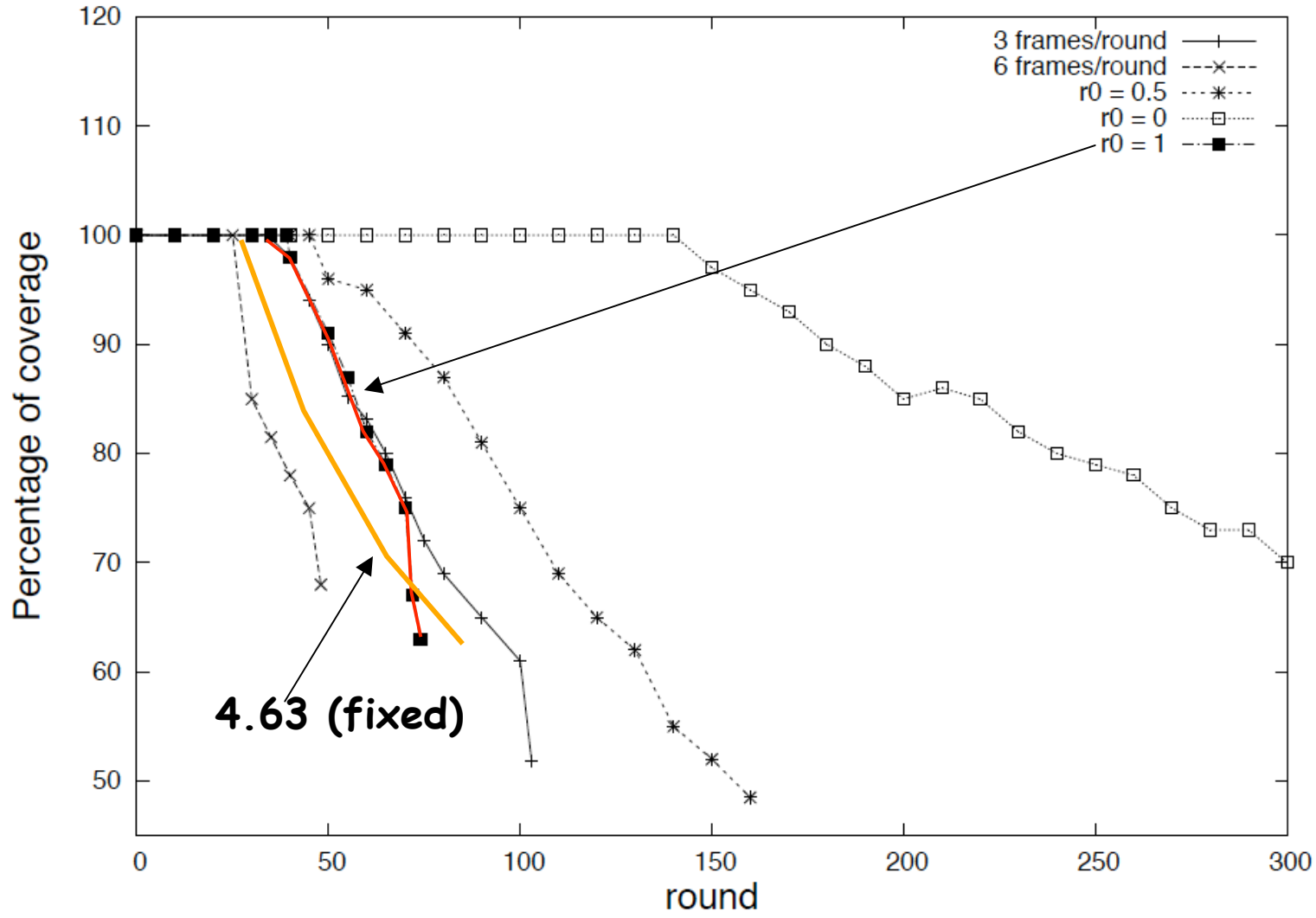
Percentage of coverage



Average capture speed



Fixed vs adaptive



Conclusions & future works

- Criticality model with adaptive scheduling of nodes
- Optimize the resource usage by dynamically adjusting the provided service level

- Extension for risk-based scheduling in intrusion detection systems
- Congestion control