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A Study on Analysis of Doppler Collision Prediction using Supervised Machine Learning

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ABSTRACT: Indian Space Research Organisation (ISRO) has developed navigation with Indian constellation (NavIC). Four geosynchronous and three geostationary satellites make up the NavIC satellite constellation. Numerous elements have an impact on the navigation system. One such issue that contributes to tracking mistakes caused by geostationary satellites is Doppler Collision. The geostationary satellite combination IRNSS 1C-1G, 1C-1F, and 1G-1F is where it occurs. Doppler Collision (DC) period is noticed when the relative Doppler frequency of the satellites is lower than the code tracking loop bandwidth. DC has an impact on the NavIC system's positioning accuracy. The geostationary satellite pair that is most impacted by DC is 1C-1G. The prediction of DC using machine learning methods will be highly helpful for increasing positioning accuracy and mitigating the DC. The geostationary satellite pair that is most impacted by DC is 1C-1G. The prediction of DC using machine learning methods will be highly helpful for increasing positioning accuracy and mitigating the DC. Relative Doppler, satellite position, satellite velocity, duration of occurrence, and relative Doppler are the factors taken into account for prediction. For prediction, K-Nearest Neighbours (KNN) regressor, Random Forest regressor, and linear regression are three supervised machine learning methods. Random Forest Regressor, one of these three algorithms, predicted the Doppler collision accurately.

KEYWORDS: Doppler Collision, Machine Learning, Navigation Systems, Satellite Signals.

I. INTRODUCTION

Navigation with Indian Constellation (NavIC), a fully operational regional satellite-based navigation system, was created by ISRO. It offers precise locating services throughout India and up to 1450 kilometres outside of national borders. Seven satellites make up the NavIC system; four of them are geosynchronous satellites and the other three are geostationary satellites [3]. IRNSS satellites 1B, 1D, 1E, and 1I are currently in geosynchronous orbit, while satellites 1C, 1F, and 1G are in geostationary orbit. There are two services offered by satellite-based navigation systems: Standard Positioning Services (SPS) and Restricted Services (RS). The NavIC system uses frequencies of 1562.42MHz, 2491.028MHz, and 1171.45MHz in the L1, S1, and L5 bands, respectively [5].

The CDMA operating system is used by the IGS receiver. Cross correlation of satellite signals causes Doppler collision. As a result, CDMA systems experience code measuring problems. Other navigation systems like GALILEO, GLONASS, and GPS are not thought to be affected by the Doppler Collision because their satellites are in a medium earth orbit and have equal Doppler frequencies, and the length of the collision will be very brief [24]. Machine learning algorithms are utilised to forecast the future incidence of Doppler collisions. To comprehend and forecast future occurrences better, machine learning is essential. A system that uses machine learning may learn things automatically and improvise based on experience without the need for outside programming [7].

II. RELATED WORK

1. Doppler Collision and cross correlation interference in GPS receivers

Authors: Asghar Tabatabaei Balaei, Dennis M Akos

Doppler collision is a physical effect in code-division multiple access (CDMA) systems where code measurement errors are observed due to cross-correlation effects. Doppler collision may occur when the Doppler frequency between signals from two different transmitters is smaller than the code lock loop bandwidth. In GPS, GLONASS, and Galileo, Doppler collision is rarely a problem because MEO satellites have equal Doppler frequencies for only very short periods. However, in systems where ground-based or geostationary transmitters are used for ranging the impact of this effect cannot be ignored [6].

2.Characterization of Doppler collision and its impact on carrier phase ambiguity resolution using geostationary satellites

Authors: Vimal Kumar Bhandari, Kyle O'Keefe

Doppler collision is a unique phenomenon in GNSS where tracking errors are introduced in the measurements due to cross-correlation between two or more satellites. It occurs when the relative Doppler frequencies of the satellites are less than the code loop bandwidth. Doppler collisions affect geostationary satellites for longer durations, due to their small line-of-sight velocities. This is a major concern for regional constellations such as IRNSS where geostationary satellites form a major part of the space segment. Doppler collision error resembles code multipath and if not mitigated could affect the ability to use pseudorange of geostationary satellites in RTK positioning. We describe likely conditions for Doppler collision, derive a Doppler collision error envelope for L1 C/A code geostationary pseudorange measurements, and then demonstrate the effect using simulated and live signals. Results indicate that the error due to Doppler collision is not purely biased and varies with a mean value close to zero. The novelty includes analysis of Doppler collision effects on an RTK solution using geostationary satellites with emphasis on ambiguity convergence time. De-weighting of geostationary observations is proposed to reduce the impact of Doppler collision [3].

3.What is Doppler Collision and is it a problem in GNSS?

Doppler collision is a physical effect in code-division multiple access (CDMA) systems where code measurement errors are observed due to cross-correlation effects. Doppler collision may occur when the Doppler frequency between signals from two different transmitters is smaller than the code lock loop bandwidth. In GPS, GLONASS, and Galileo, Doppler collision is rarely a problem because MEO satellites have equal Doppler frequencies for only very short periods. However, in systems where ground-based or geostationary transmitters are used for ranging the impact of this effect cannot be ignored [27].

4.Predictive Data Optimization of Doppler Collision Events for NavIC system

AUTHORS: Sathish P, Krishna Reddy D

Navigation with Indian Constellation (NavIC) is satellite-based navigation system developed by Indian Space Research Organization (ISRO), India. It consists of seven satellites, among them, three are geostationary (GEO) satellites, and the rest are geosynchronous satellites. There are several factors that effect the positional accuracy of the NavIC system, and among them, one of the important parameter is Doppler collision (DC). The occurrence of the DC depends upon the usage of geostationary (GEO) satellites in position estimation. The DC may occur when the relative Doppler shift between two satellites is less than the bandwidth of receiver code tracking loop. To analyze the DC events, the required navigational data are collected from IRKS-GPS-SBAS (IGS) receiver located at low latitude station. There are variations in the values of Doppler shift of GEO satellites and have a significant impact on the Doppler collision prediction. To predict the DC accurately, the data optimization is very much essential for precise positioning applications. This paper presents the predictive data optimization of DC events by using various filtering methods such as moving average, Savitzky-Golay and median filter. Among three methods, Savitzky-Golay method provides better data optimization to predict short-term DC events as compared with other methods [35].

5. Understanding GPS Principles and Applications

AUTHORS: Elliott, D. Kalpan

This thoroughly updated second edition of an Artech House bestseller brings together a team of leading experts who provide a current and comprehensive treatment of the Global Positioning System (GPS). The book covers all the latest advances in technology, applications, and systems. The second edition includes new chapters that explore the

integration of GPS with vehicles and cellular telephones, new classes of satellite broadcast signals, the emerging GALILEO system, and new developments in the GPS marketplace. This single-source reference provides a quick overview of GPS essentials, an in-depth examination of advanced technical topics, and a review of emerging trends in the GPS industry [49].

III. EXISTING SYSTEM

In Existing system, the Most of the time additional protection is provided by the fact that each received signal has its own Doppler frequency offset as the result of each tracked satellite having a different range rate with respect to the receiver [51]. However, if the difference between the Doppler frequencies from two different satellites is small enough, the cross-correlation peaks may interfere with the primary peaks and cause tracking errors. The tracking errors are similar to multipath in that a secondary correlation peak is distorting the main peak [63].

DISADVANTAGES :

- ❖ When two geostationary transmitters the cross-correlation amplitude creates a hyperbolic interference pattern that in low- and mid-latitudes is approximated by north-south running stripes where cross-correlation occurs.
- ❖ Doppler collision results in a multipath-like bias in the code measurement that can last for minutes to hours, using code measurements from these geostationary satellites to estimate the corresponding carrier phase ambiguities is risky.
- ❖ Algorithm: Pseudo Random Noise (PRN) codes [54].

IV. PROPOSED SYSTEM

In the proposed system Supervised Machine Learning is used in predicting the future Doppler Collision events. To train the model, supervised machine learning uses labeled data [43]. The model is trained by knowing the object features and labels in relation with those features. Three regression based supervised machine learning algorithms are used for predicting Doppler Collision events. The regression-based algorithm is used to predict a continuous output for an input based on previous data. The value of multiple predictor variables given to the model are satellite position of 1C-1G, in our model we combined both in a single dataset its velocities and occurrence period (seconds) and the relative Doppler is given as an output variable [68].

ADVANTAGES OF PROPOSED SYSTEM:

- K-Nearest Neighbors model gives a constant relative Doppler as an output as there is a class imbalance in the input parameters [57].
- Random Forest model improves its accuracy by using averaging technique for predicting Doppler Collision [48].
- Linear Regression model gives negative relationship between the parameters as value of independent variable increases, the value of dependent variable decreases.
- Algorithm: Logistic Regression, Random Forest, KNN [32].

V. IMPLEMENTAION

User:

The User can register the first. While registering he required a valid user email and mobile for further communications. Once the user register then admin can activate the user. Once admin activated the user then user can login into our system. User can upload the dataset based on our dataset column matched. For algorithm execution data must be in float format. Here we took doppler collision dataset. User can also add the new data for existing dataset based on our Django application. User can click the Classification in the web page so that the data calculated MAE, MSE, R2-score, RMSE based on the algorithms [54].

Admin:

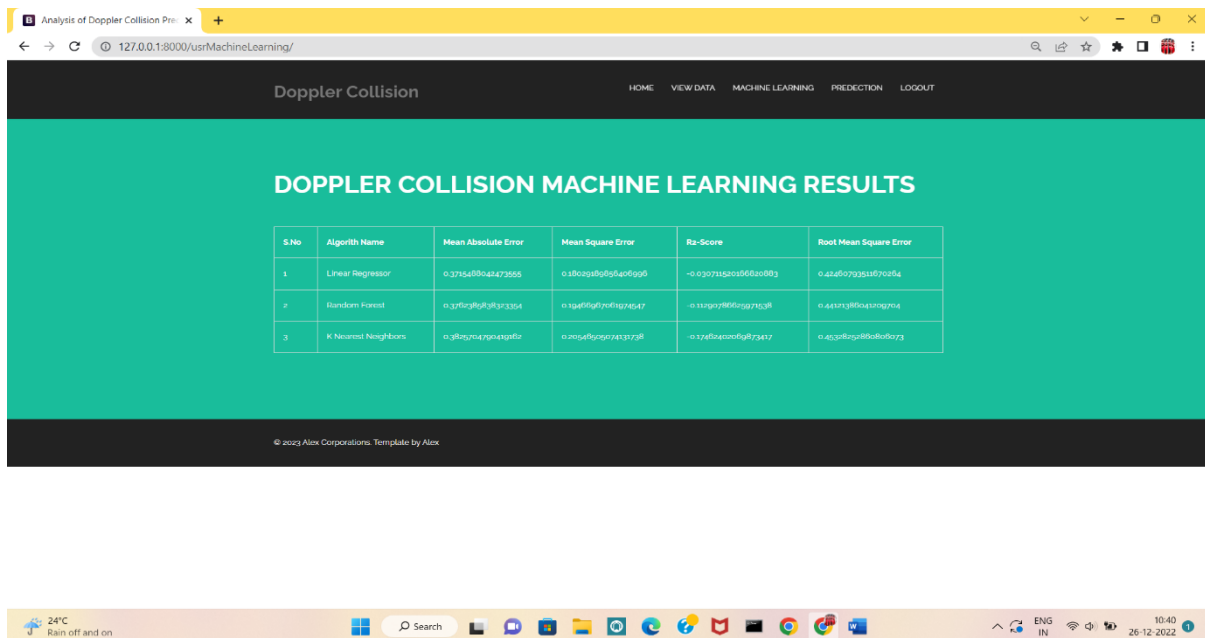
Admin can login with his login details. Admin can activate the registered users. Once he activate then only the user can login into our system. Admin can view the overall data in the browser. Admin can click the Results in the web page so calculated MAE, MSE, R2-score, RMSE based on the algorithms is displayed. All algorithms execution complete then admin can see the overall accuracy in web page [76].

Data Pre-processing:

A dataset can be viewed as a collection of data objects, which are often also called as a records, points, vectors, patterns, events, cases, samples, observations, or entities. Data objects are described by a number of features that capture the basic characteristics of an object, such as the mass of a physical object or the time at which an event occurred, etc. Features are often called as variables, characteristics, fields, attributes, or dimensions. The data preprocessing in this forecast uses techniques like removal of noise in the data, the expulsion of missing information, modifying default values if relevant and grouping of attributes for prediction at various levels [82].

Machine Learning Results:

Based on the split criterion, the cleansed data is split into 60% training and 40% test, then the dataset is subjected to six machine learning regressor such as Random Forest (RF), K-Nearest Neighbour(KNN), Linear Regression (LR). The accuracy of the classifiers was calculated and displayed in my results. The classifier which bags up the highest MSE could be determined as the best regression [97].



VI. CONCLUSION AND FUTURE WORK

In the analysis of predicting Doppler Collision, it has been found that Random Forest Regression has the least RMSE value which means that it is more efficient when compared to other two algorithms [109]. The RMSE of Linear Regression model is 1.15 for first Doppler Collision period and RMSE for second Doppler Collision period is 3.43. The RMSE value for first, second Doppler Collision period is 0.56, 0.47 respectively using Random Forest regressor model. The RMSE value of K-Nearest Neighbors regressor model is 0.51 for first Doppler Collision period and RMSE for second Doppler Collision period is 0.46. The Doppler Collision occurrence between 1C & 1G for event 1 is 1 hour 3 minutes 25 seconds and for Doppler Collision event 2 is 1 hour 13 minutes and 13 seconds. It is observed that Time and Satellites position, velocity are in correlation with relative Doppler. Further, this work can be extended by applying digital filters with Machine Learning algorithms to improve RMSE value.

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