

# Mobility Modeling

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Master RES – Nouveaux Réseaux et Services



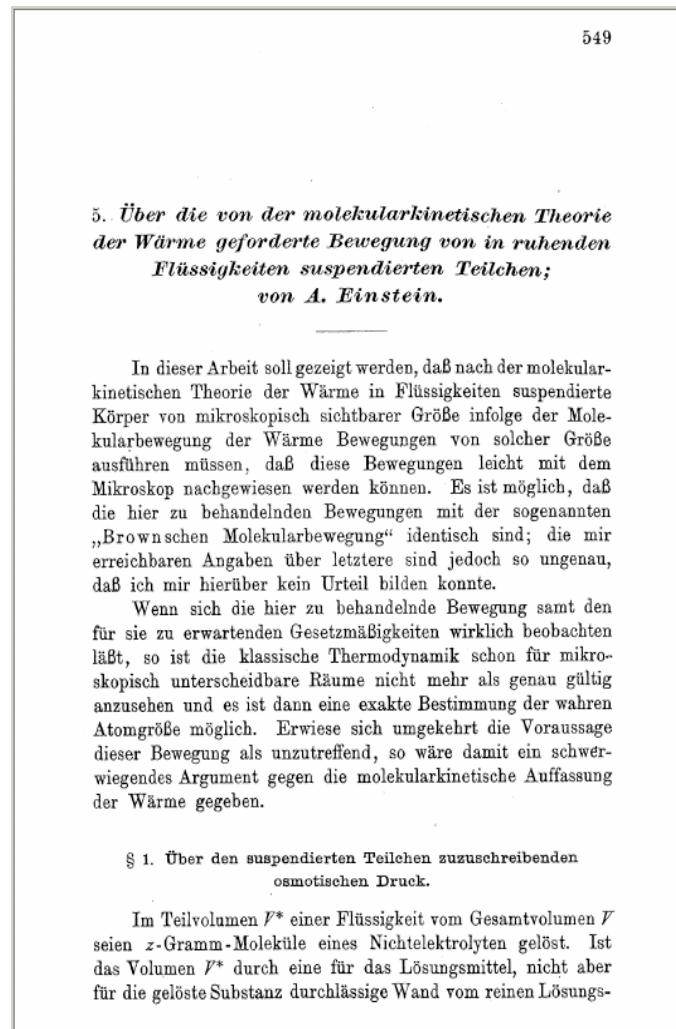
# Outline

- Introduction
  - Rationale, Classification, State-of-art
- Mobility Models
  - From random to more realistic models
- Performance evaluation
  - Analytical vs. Simulations vs. Traces vs. Experiments
- System design
  - Designing better communication systems
- Outlook, demos and conclusion

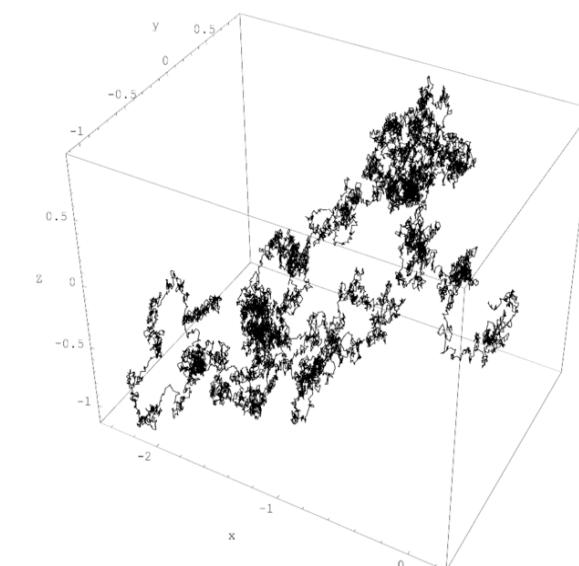
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# It all started with Einstein's Brownian motion

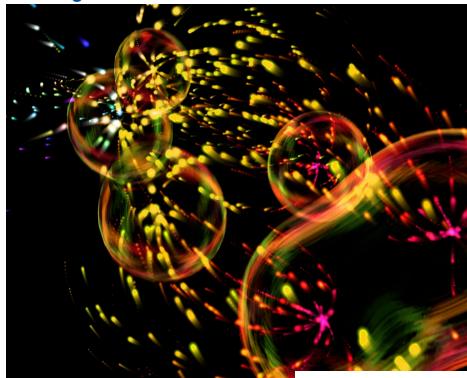


- “Investigations on the theory of Brownian movement”
- To indirectly confirm the existence of atoms and molecules



# Many domains

## Physics



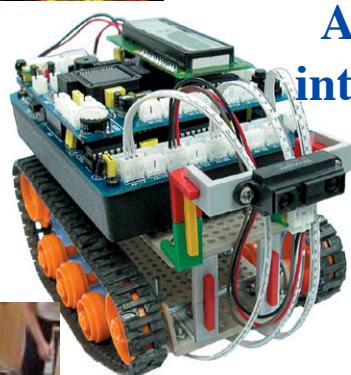
## Transportation systems



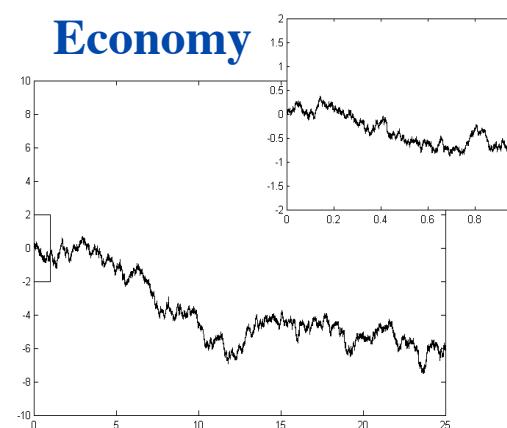
## Biology



## Artificial intelligence



## Economy

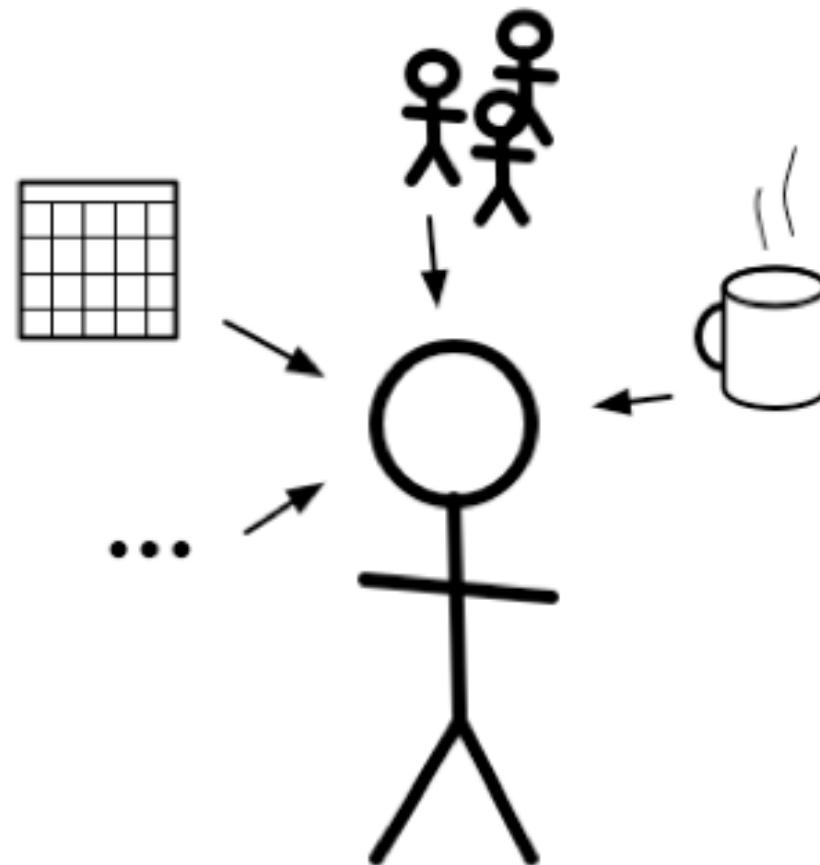


## Architecture



## Gaming

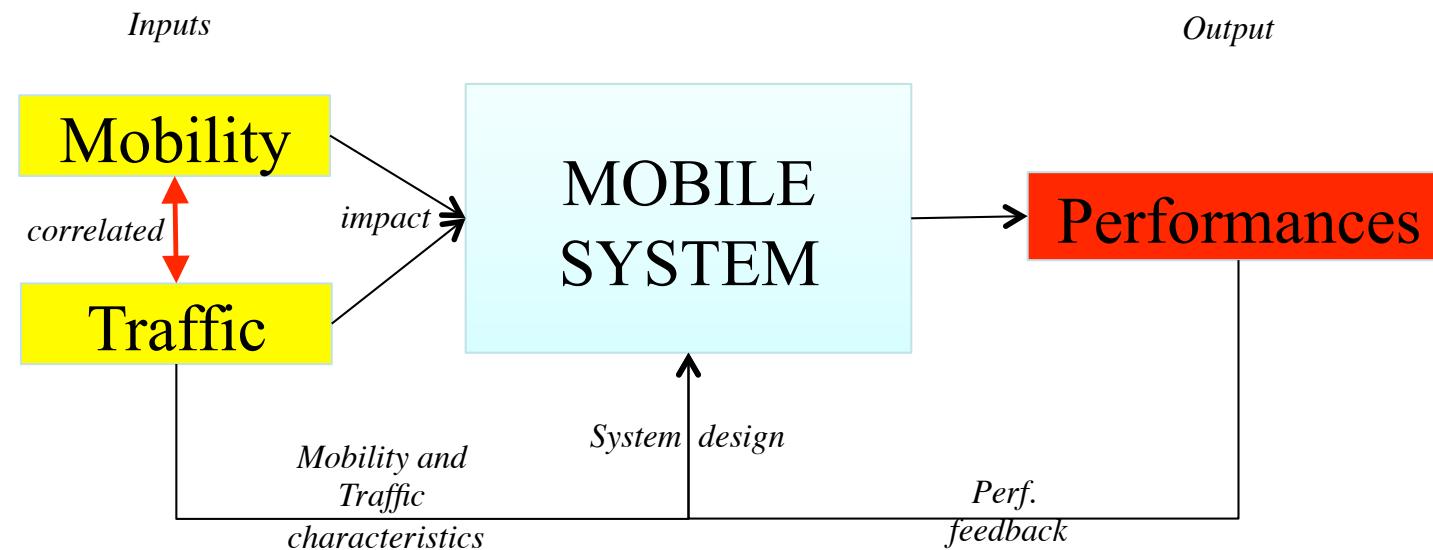
# Understanding mobility is complex



## Rationale for Mobility Models

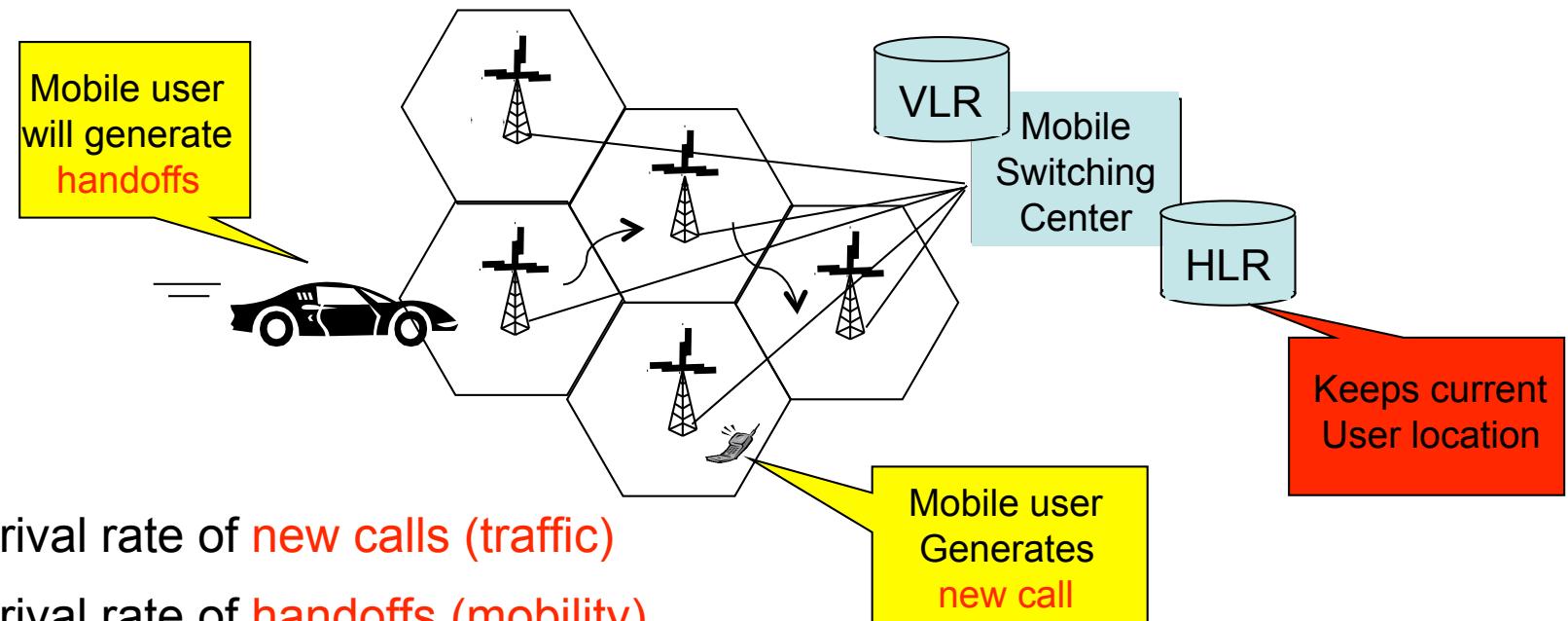
- Mobility Models are required for
  - **Performance evaluation**
    - Analytical
      - A system dynamics must be tractable in order to derive characteristics of interest
    - Simulations
      - Often used as an alternative when models are too complex (no analytical derivation)
      - But still complementary to the analytical approach
    - Trace-replaying and experiments
  - **Solution design**
    - Networking solutions should be designed according to their *in situ* environment (i.e., mobility context and characteristics)

## Rationale for Mobility Models (cont'd)



# Evaluation of Cellular Networks

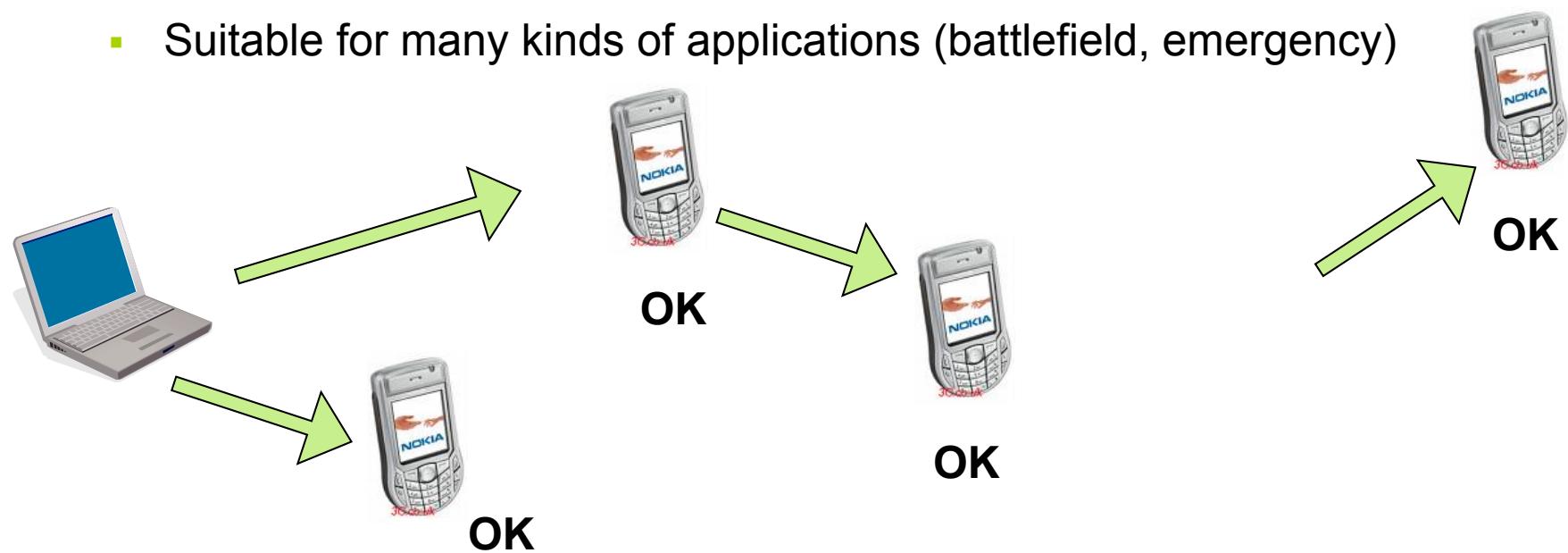
- Aim at providing integrated communications (i.e., voice, video, and data) between nomadic subscribers in a seamless fashion



- Input
  - Arrival rate of **new calls** (traffic)
  - Arrival rate of **handoffs** (mobility)
- Output
  - HLR load, probability of call rejection

## Evaluation of Ad Hoc and Delay Tolerant Networks

- A wireless ad hoc network is a decentralized wireless network
  - Suitable for many kinds of applications (battlefield, emergency)



- Input
  - Both ends can move: mobility highly impacts the performances
- Output
  - Path duration from source to destination? Delay?

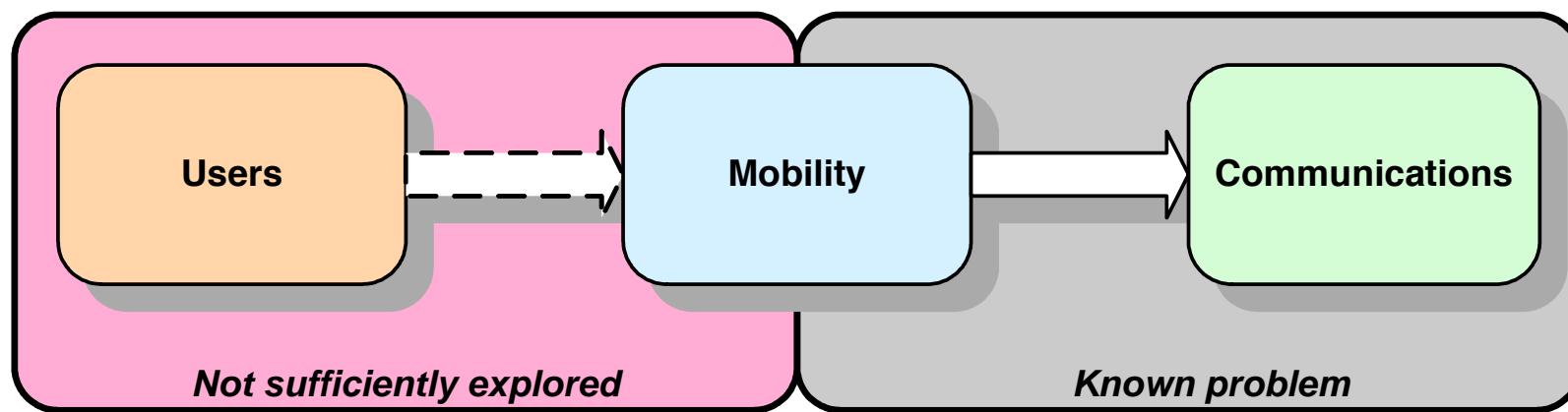
# Classification of Mobility Models

- Scale
  - Microscopic
    - accurately describes the motion of mobile individuals
  - Macroscopic
    - considers the displacement of mobile entities (e.g., pedestrians, vehicles, animals) at a coarse grain, for example in the context of large geographic areas such as adjacent regions or cells
- Formalism
  - Flow
  - Fluid (fluid-like PDE)
  - Stochastic (Markov, ODEs, Queuing)
  - Behavioral (non-linear)

## Classification vs. Applications

	Macro	Micro-Macro		Micro
Applications	Cellular networks (e.g., PCS, 3G/4G)	Self-organizing networks (e.g., ad hoc, delay-tolerant, sensor, mesh)		
Level-of-detail	Low	Medium		High
Approaches (examples)	Markovian Fluid Gravity	<i>Synthetic</i> : RWP, RPBM City Section	<i>More Realistic</i> : Campus, Vehicular	Smooth RWP, Behavioral

# The current situation in networking



*Courtesy of Prof. Ammar*

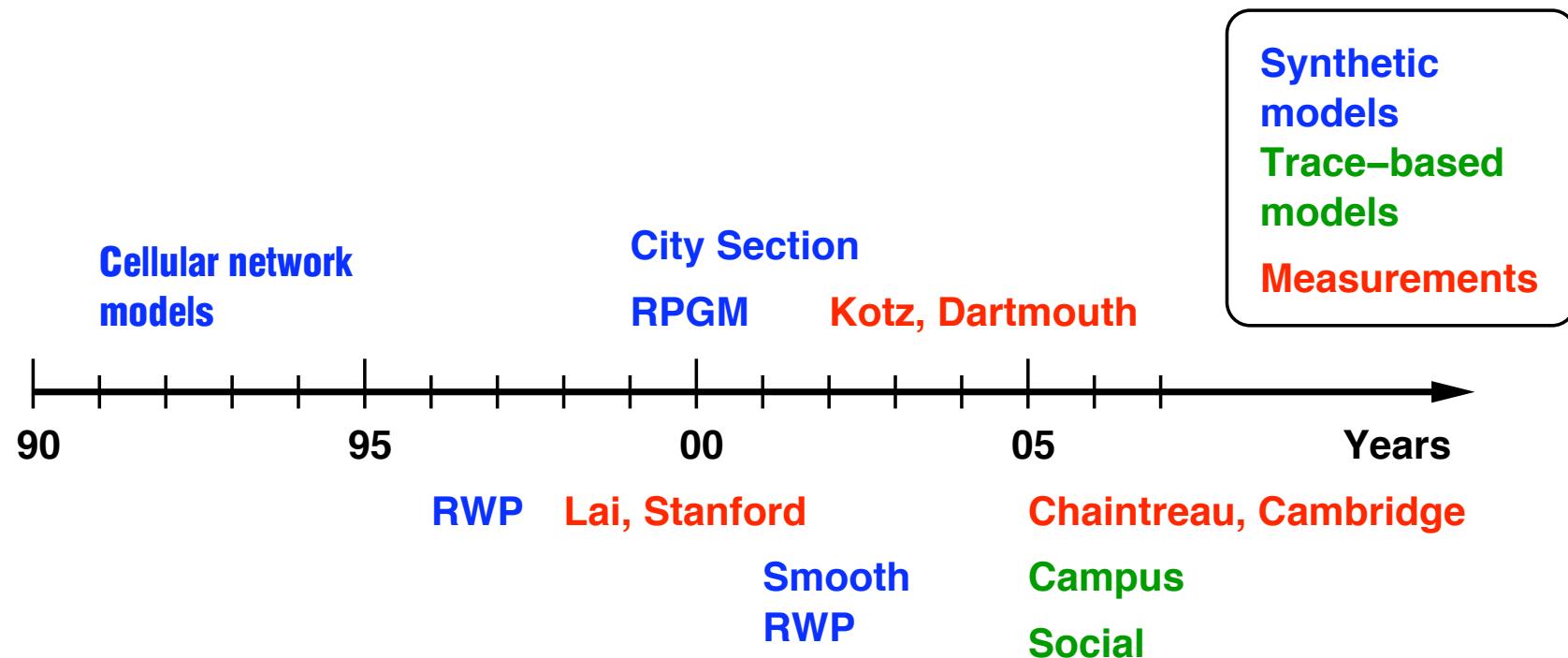
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## Mobility Models – From Random to more Realistic

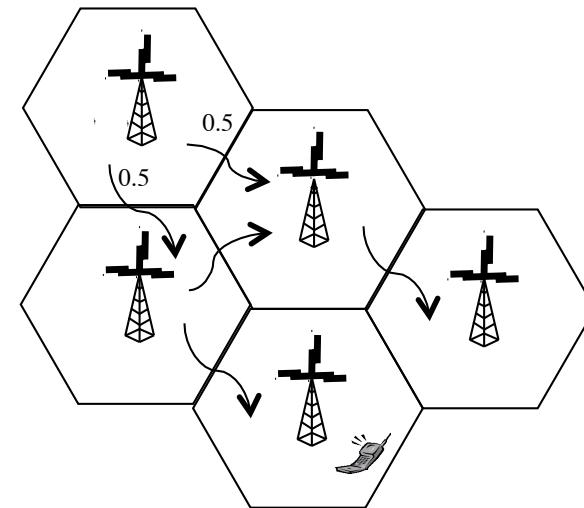
- Cellular models
- Random Mobility models (synthetic) [**Camp02Survey**]
  - Ad Hoc
  - Vehicular
- More realistic mobility models
  - Extension of random models
  - Behavioral models: Ad Hoc, Vehicular [**Haerri06Survey**], Social
  - Survey and Trace-based models

# Mobility Models – Review



## Cellular model – Markovian

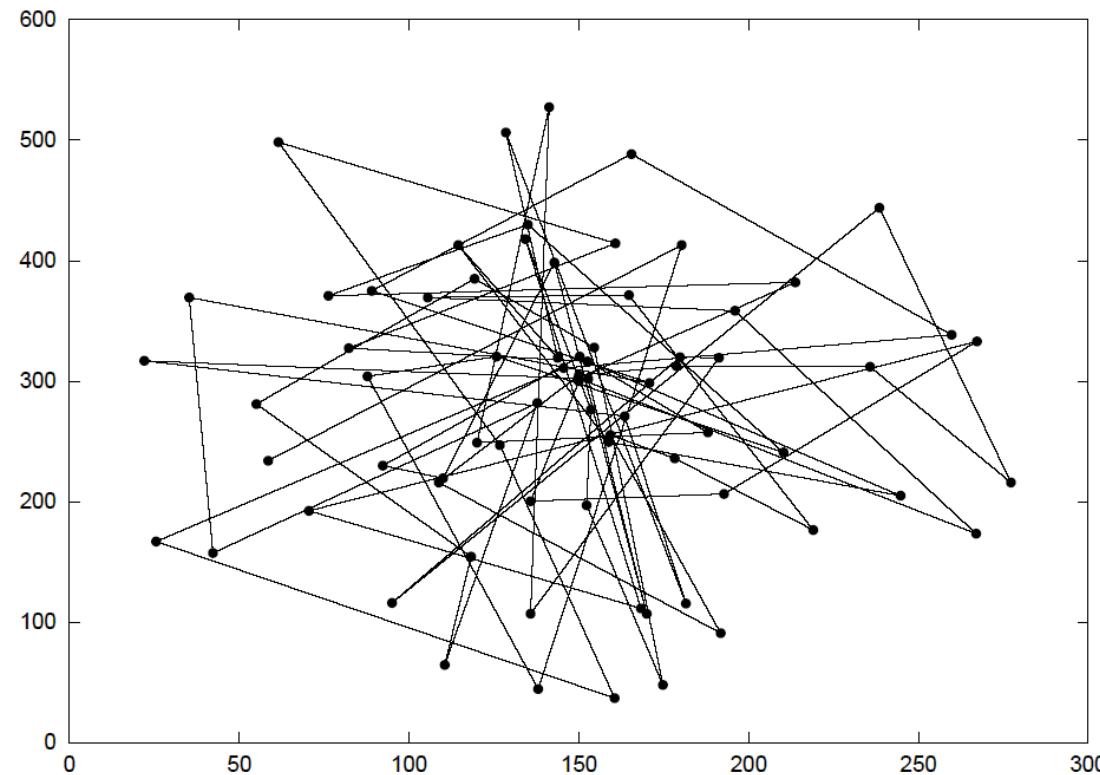
- Each transition from a cell  $i$  to  $j$  has a defined probability



## Synthetic model – Random Walk

- Based on Einstein Brownian Motion
- A mobile node moves from its current location to a new location by randomly choosing a direction and speed in which to travel
  - The new speed and direction are both chosen from pre-defined ranges,  $[speedmin; speedmax]$  and  $[0; 2\pi]$  respectively
  - Each movement in the Random Walk Mobility Model occurs in either a constant time interval  $t$  or a constant distance traveled  $d$
  - At the end of a move, a new direction and speed are calculated
  - If an MN which moves according to this model reaches a simulation boundary, it “bounces” off the simulation border with an angle determined by the incoming direction

## Synthetic model – Random Walk (cont'd)



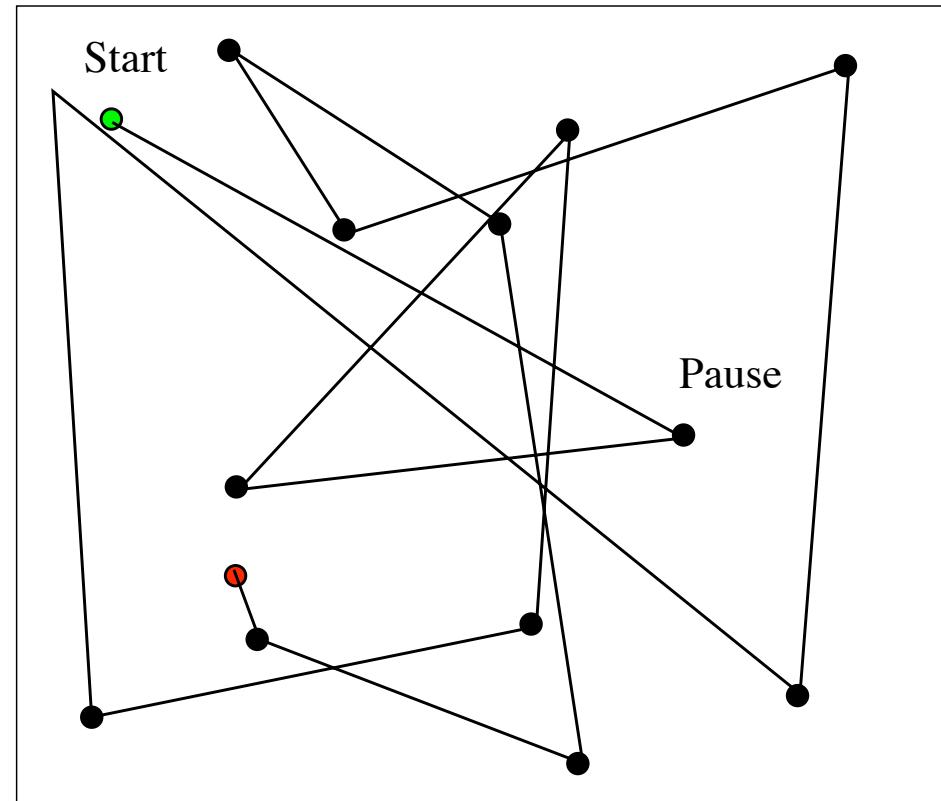
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Trajectory of one MN under Random Walk

## Synthetic model – Random Waypoint (RWP)

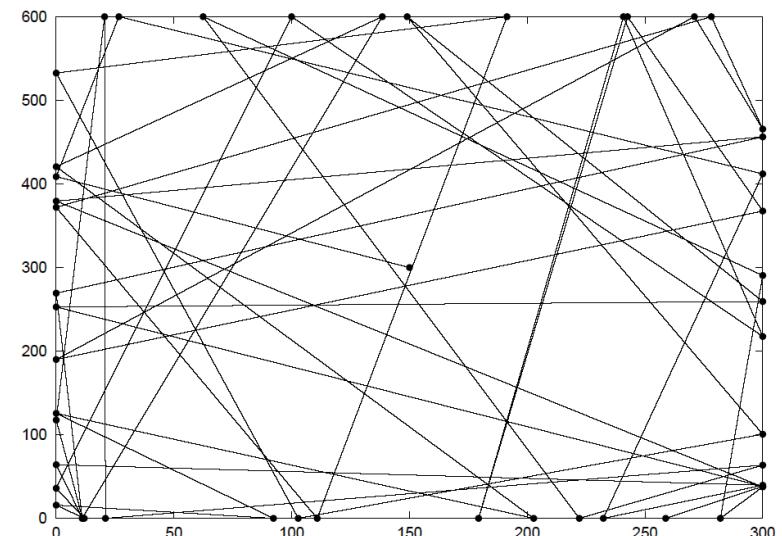
- An MN begins by staying in one location for a certain period of time (i.e., a pause time)
- Once this time expires, the MN chooses a random destination in the simulation area and a speed that is uniformly distributed between  $[minspeed, maxspeed]$
- The MN then travels toward the newly chosen destination at the selected speed
- Upon arrival, the MN pauses for a specified time period (uniformly distributed between  $[minpause, maxpause]$ ) before starting the process again

## Synthetic model – Random Waypoint (RWP) (cont'd)



## Synthetic model – Random Direction (RD)

- A mobile node chooses a random direction in which to travel similar to the Random Walk Mobility Model. The node then travels to the border of the simulation area in that direction
- Once the simulation boundary is reached, the node pauses for a specified time, chooses another angular direction (between 0 and 180 degrees) and continues the process



Trajectory of one MN under Random Direction

## Synthetic model – Characteristics of Random models

- All are derived from Einstein's Brownian Motion
  - Mathematically tractable
  - Memory-less
- Problems of simple random models
  - No preferred locations in space domain (uniform nodal distribution across space)
  - No structure in time domain (homogeneous behavior across time)
  - No collective behavior (i.e., group mobility, gatherings)

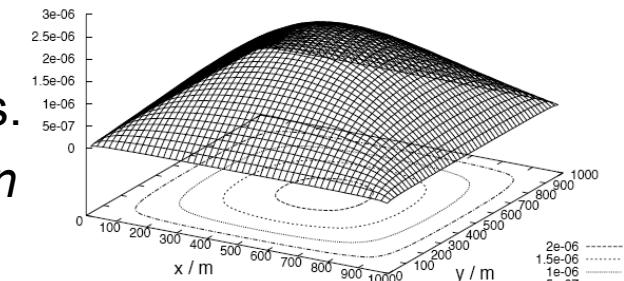
## Mobility Models – Analytical derivation

- The case of RWP [Bettstetter02Spatial]
  - Theorem: A node moves on a line  $[-x_m, x_m]$  according to a one-dimensional RWP model with constant speed and uniformly distributed destination points. The probability density function  $f_x(x)$  of its location given by

$$f_x(x) = -\frac{3}{4x_m^3}x^2 + \frac{3}{4x_m}, \quad -x_m \leq x \leq x_m$$

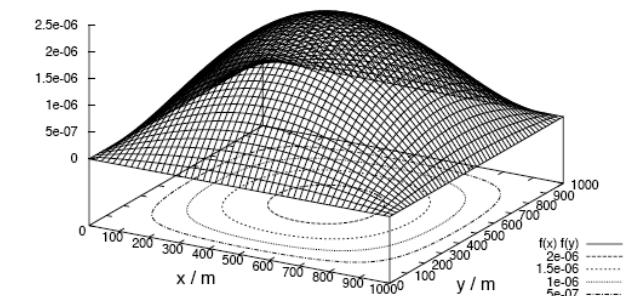
- Assuming a 2D RWP movement in a square area consisting of two independent one-dimensional movement processes along the  $x$  and  $y$  axes, we have:

$$f(x)f(y) = -\frac{9}{16x_m^3y_m^3}(x^2 - x_m^2)(y^2 - y_m^2)$$



a. Square simulation area

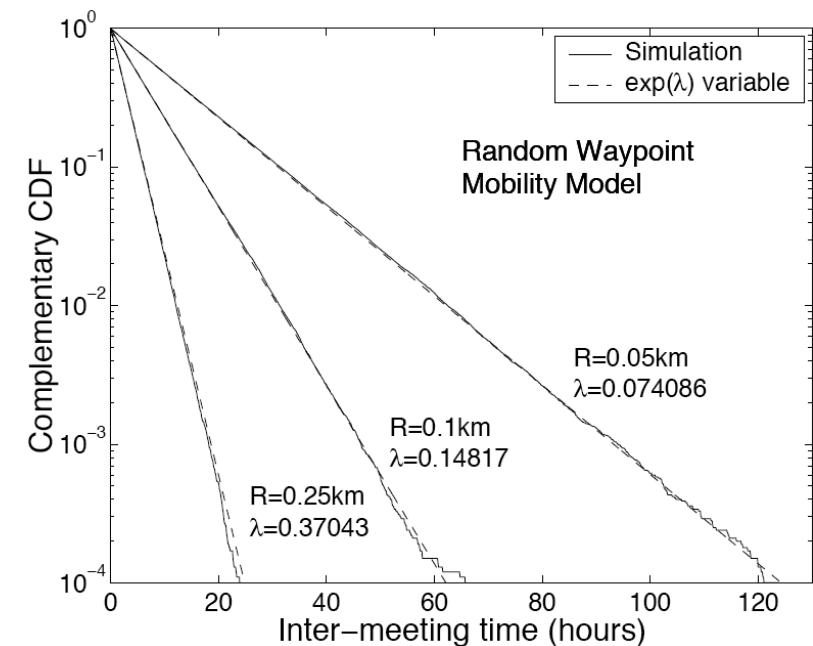
Simulations (up) vs.  
analytic (down)



a. Square simulation area:  $f(x)f(y)$

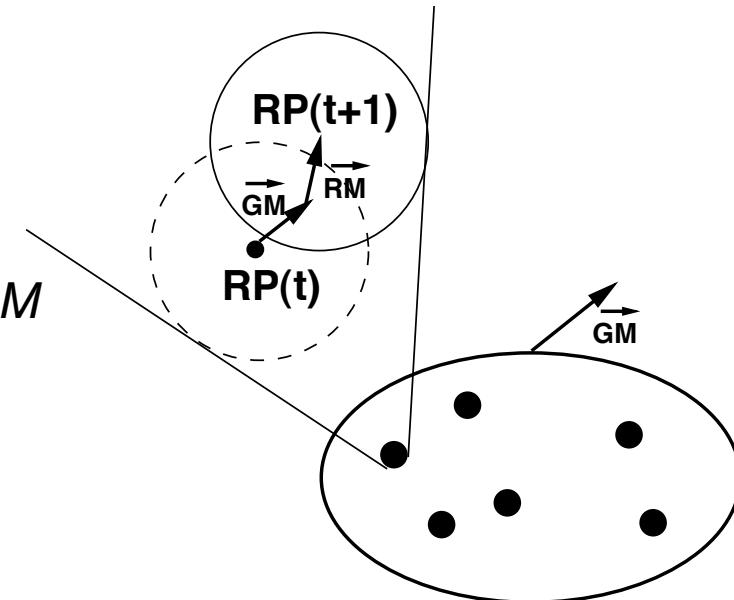
## Mobility Models – Analytical derivation

- The case of RWP and Random Direction [**Groenvelt05Message**]
  - The inter-contact rate is approximated by
 
$$\lambda \approx \frac{2 \omega r E[V^*]}{L^2}$$
    - $\omega$  is a constant specific to the mobility model
      - $\omega = 1.3683$  for RWP
      - $\omega = 1$  for RD
    - $r$  communication range
    - $E[V^*]$  is the average relative speed between two nodes
    - $L$  length of square area
  - See also [**Sharma04Scaling**]

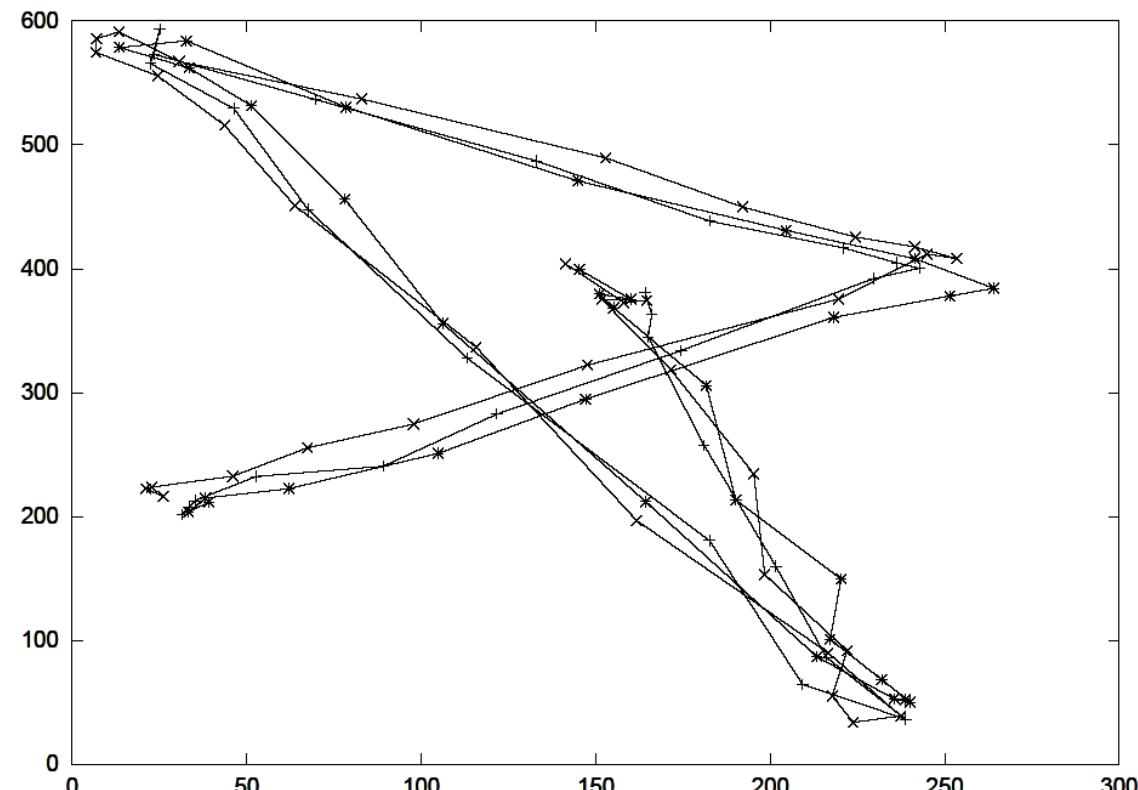


## Synthetic model – Reference Point Group Mobility

- The Reference Point Group Mobility (RPGM) model represents the random motion of a group of nodes as well as the random motion of each individual MN within the group
  - A logical center for the group is used to calculate group motion via a group motion vector,  $GM$
  - This logical center follows RWP
  - Individual nodes randomly move about their own pre-defined reference points combined with a random motion vector,  $RM$



## Synthetic model – Reference Point Group Mobility



Trajectory of one group (three MN) under RPGM

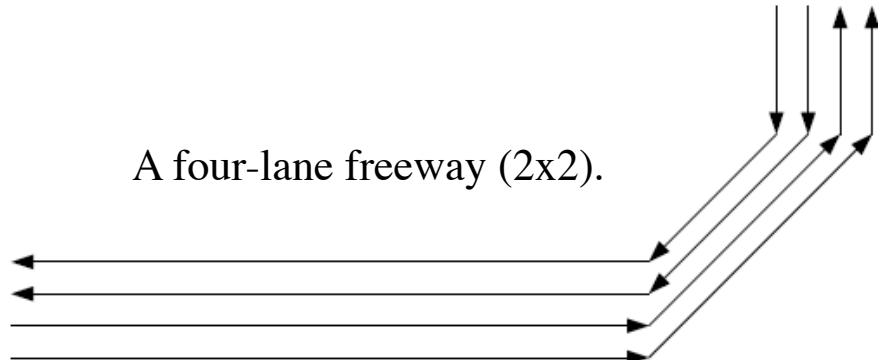
## Synthetic vehicular model – Freeway [Bai03Important]

- Models the behavior of vehicles traveling on a freeway

**[Bai03Important].** The movement of a node is restricted to a lane of a freeway and is temporally dependent on the previous speed and other vehicles travelling in front on the same lane

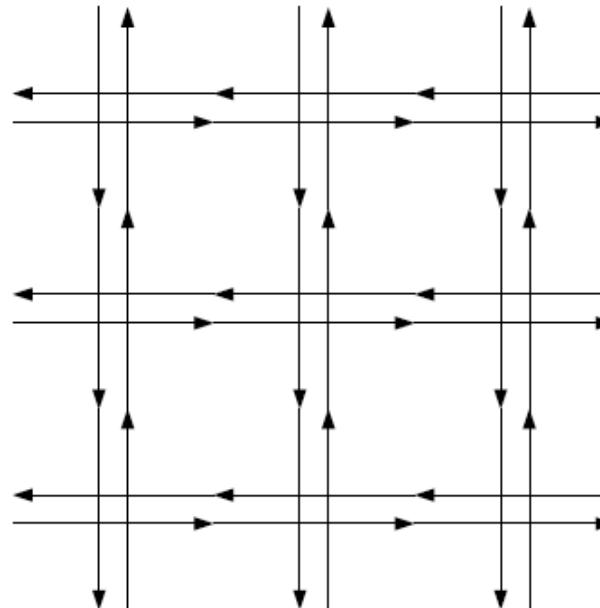
- Speed update:  $v_i(t + 1) = v_i(t) + \text{random}() * a_i(t)$ 
  - where  $a_i$  is the acceleration of node  $i$
  - $\text{random}() \sim U[-1,1]$  adds some noise
- Speed of  $i$  is limited by  $j$  in front:  $d(i, j) \leq d_{\text{safety}} \Rightarrow v_i(t) \leq v_j(t)$ 
  - where  $d_{\text{safety}}$  is the safety distance

A four-lane freeway (2x2).



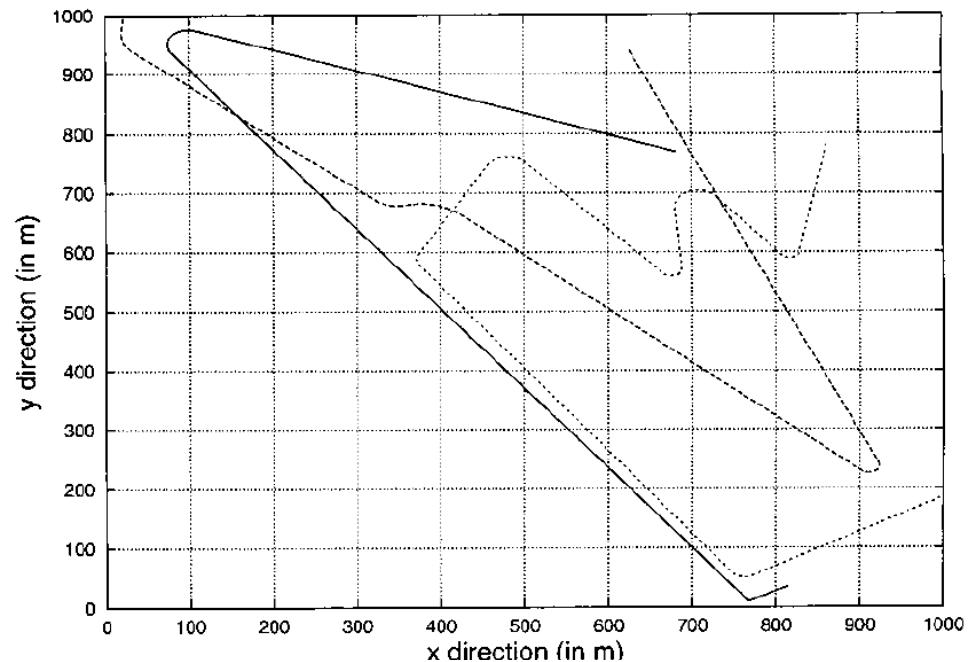
## Synthetic vehicular model – Manhattan [Bai03Important]

- Nodes move on a grid
  - At each intersection, it randomly selects the street it will follow
    - 0.5 straight, 0.25 right, 0.25 left
  - Nodes behave similarly to the freeway model
  - Nodes *can* pause at intersections



## More Realistic – Extension of Random models

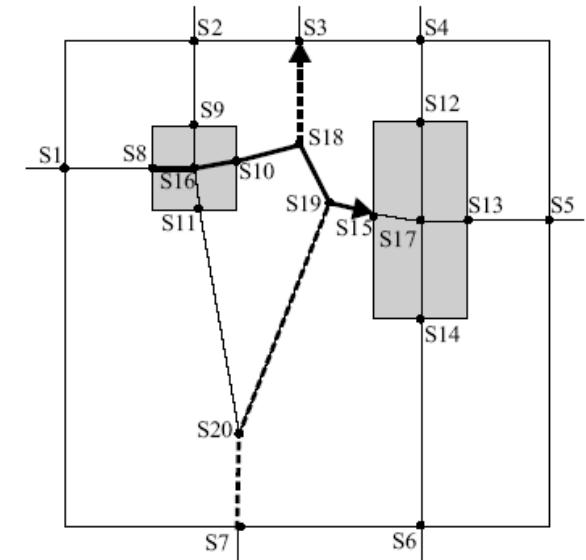
- Smooth RWP [Bettstetter00Modeling]
  - RWP with smooth turning
  - Slowdown when turning
  - Accounts for car behavior in cities



Three Smooth RWP traces

## More Realistic – Campus

- Campus Model with obstacles [Jardosh05Real]
  - Voronoi diagram is used to determine the path of mobile nodes
    - Planar graph whose edges are line segments that are equidistant from two obstacle corners
  - A variation of RWP
    - The environment limits the trajectories of mobile nodes to the Voronoi graph
    - Shortest-path is computed on this graph between S-D

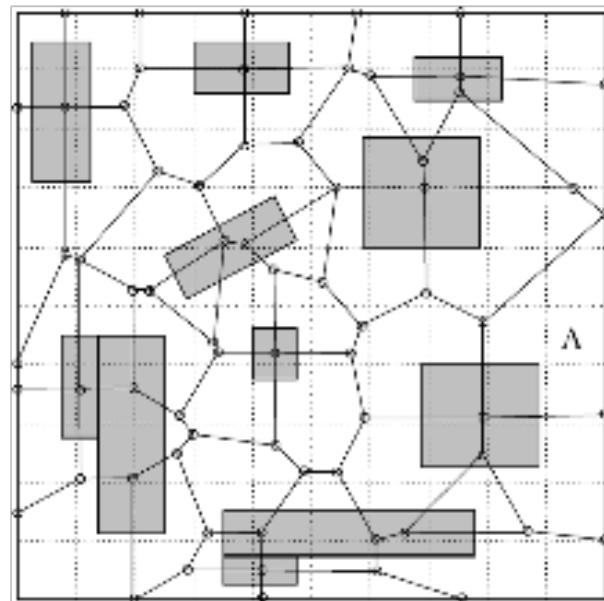


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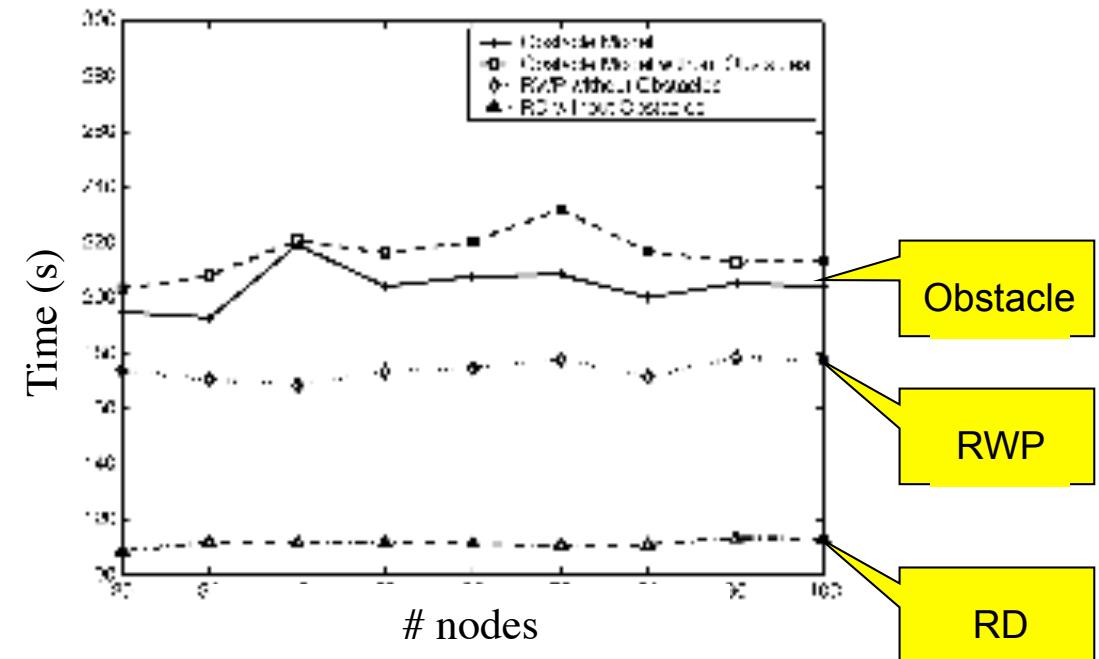
Example of trajectories  
S8->S15 and S7->S3.

## More Realistic – Campus (Cont'd)

- Radio propagation model accounts for obstacles
  - Signal fading model with factor depending on the relative node position and type of obstacle that lie in the path between the two nodes



Simulated terrain



Average link duration

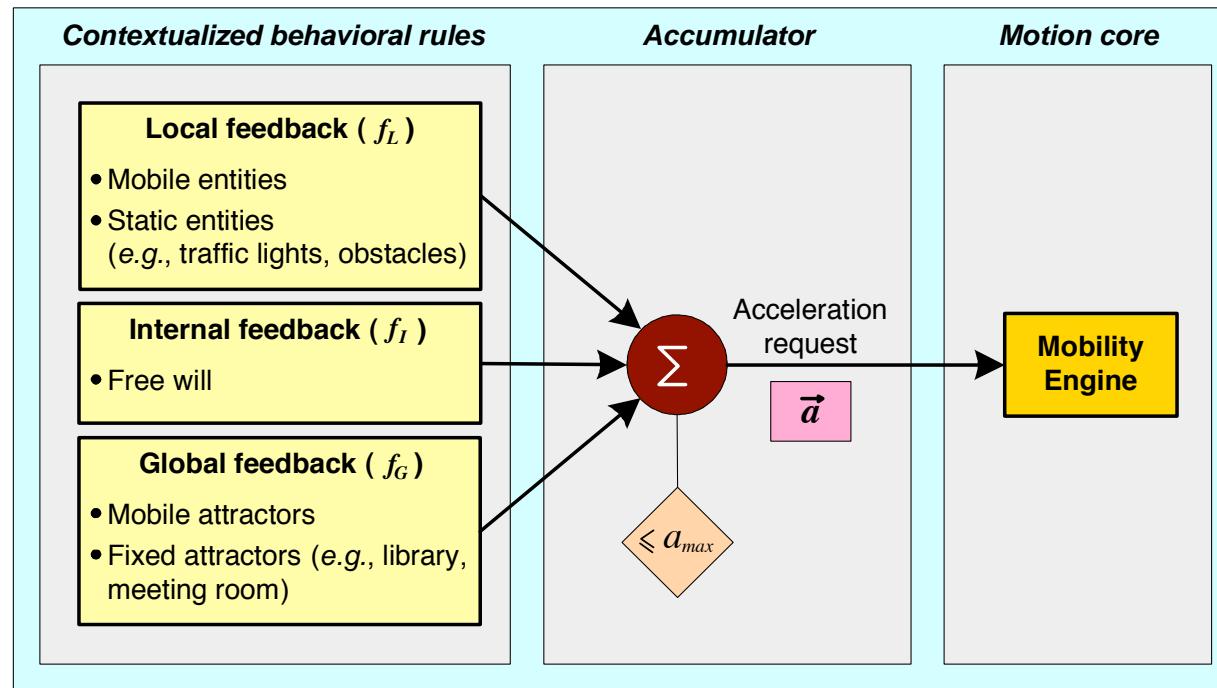
## More Realistic – Behavioral Models (BM)



- Behavioral models: decompose mobility into atomic rules
  - **At the local scale**: avoid obstacles, walls, other peers (pedestrian, vehicle), **stay in group** (e.g., fish/bird flocks **[Reynolds87Flocks]**)
  - **At the global scale**: take the shortest path, join group of friends
- Main characteristics
  - Accounts for **interactions** (non-linear)
  - Emergent behaviors (trait of complex BM models)
- Three examples
  - At the micro-scale: vehicular, pedestrians
  - At the macro-scale: social model of crowd motion

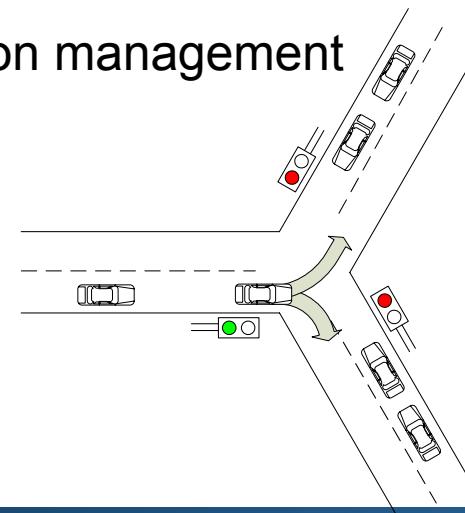
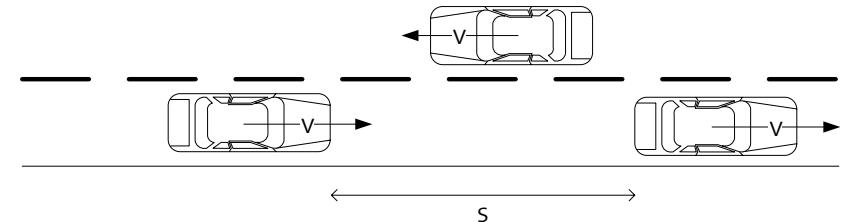
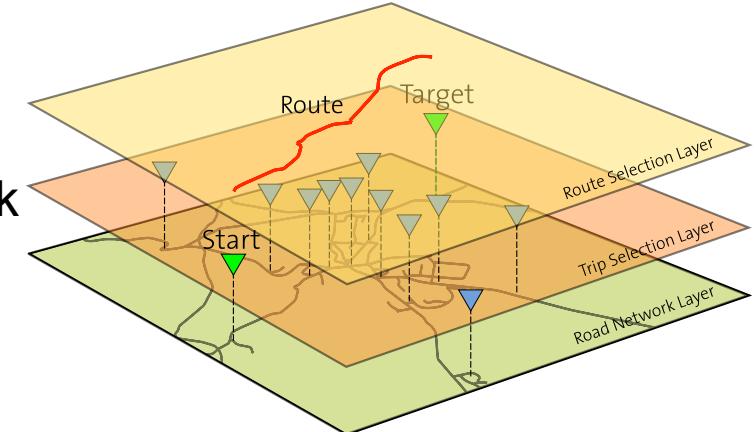
## More Realistic – Behavioral Models (cont'd)

- From behavioral rules to motion
  - Behavioral rules**: output acceleration requests
  - Accumulator**: combines rules
  - Motion core**:  $\vec{v}(t + \Delta t) = \vec{v}(t) + \vec{a}\Delta t$



## More Realistic – Vehicular behavioral Models

- Global behavioral rule (*global feedback*)
  - Pre-trip: RWP but constraint to road network
- Local behavioral rules (*local feedback*)
  - Speed adjustment and Car-following
  - Intersection management



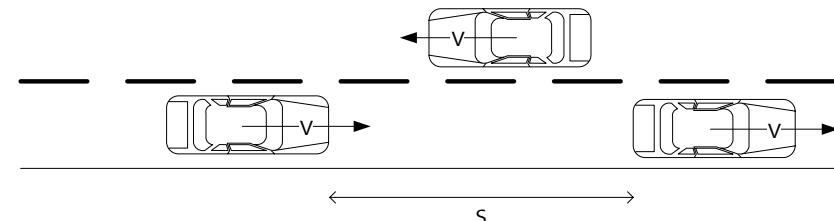
## More Realistic – Vehicular behavioral Models

- Intelligent Driver Model (IDM) [Helbing00Congested]
  - The speed of vehicle depends on the current speed  $v$ , the desired speed  $v_0$ , the distance to the front vehicle  $s$ , and desired safety distance  $s^*$

$$\frac{dv}{dt} = a \left[ 1 - \left( \frac{v}{v_0} \right)^\delta - \left( \frac{s^*}{s} \right)^2 \right]$$

1
2

- with  $s^* = s_0 + \left( vT + \frac{v\Delta v}{2\sqrt{ab}} \right)$

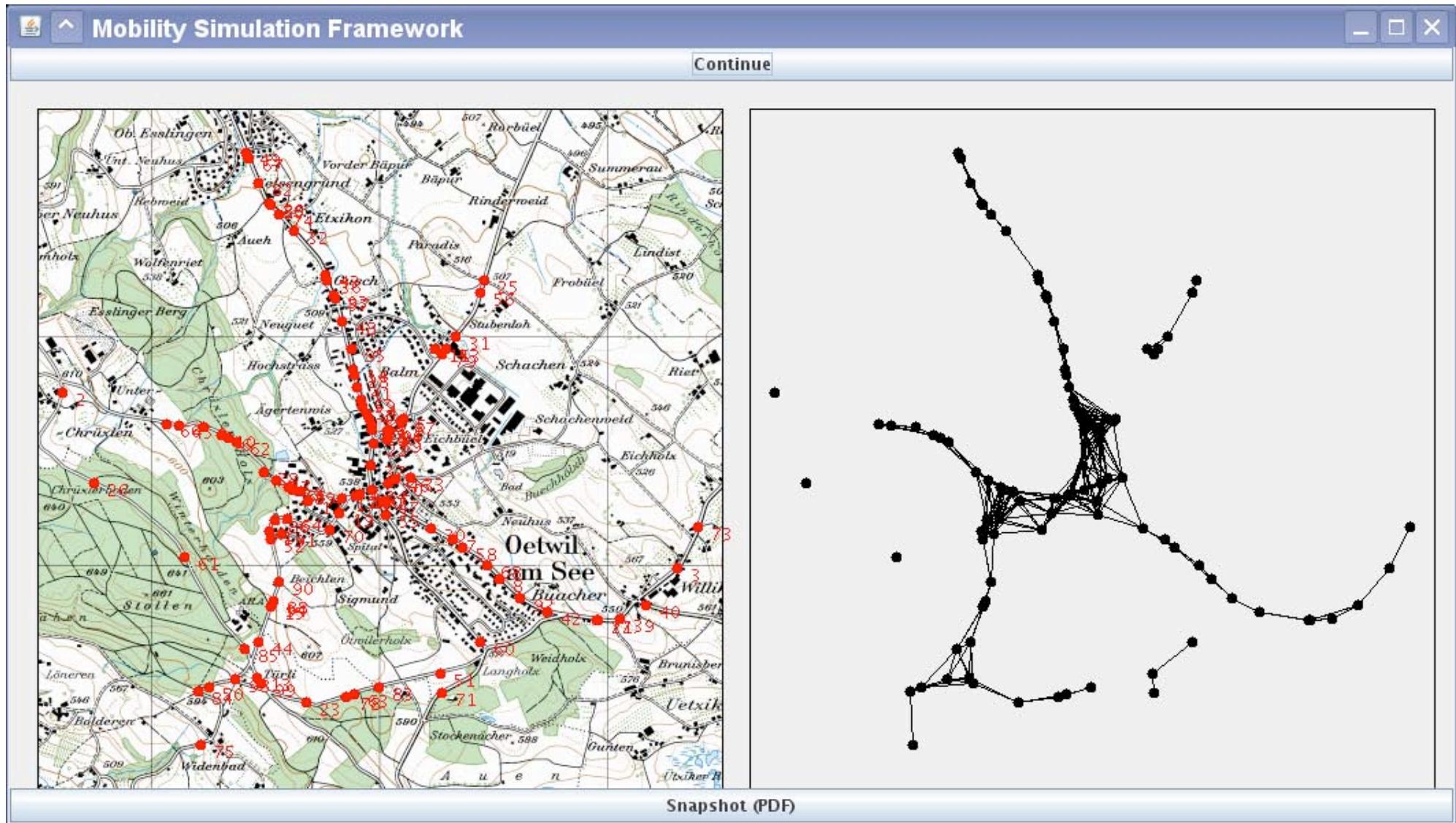


Parameter	Description	Value
$v_0$	Desired speed	speed limit
$a$	Acceleration constant	0.6
$b$	Deceleration constant	0.9
$T$	Reaction time	0.5 s
$s_0$	Minimal gap between vehicles	1 m

Table 2: Local behavioral rules parameters.

- 1 Free-road term (accelerates until speed limit is reached)
- 2 Breaking term (is 0 when no vehicle ahead)

# More Realistic – Vehicular behavioral Models



# More Realistic – Behavioral pedestrian motion

## [Helbing00Escape, Legendre06Reconsidering]

- Global behavioral rule (*global feedback*)
  - Take shortest path
- Local behavioral rules (*local feedback*)
  - *Avoid walls*: repulsive force (normal to wall)
  - *Avoid obstacles*: pass by nearest obstacle edge minimizing detour to avoid obstacle
  - *Mutual avoidance*: keep safety distance
  - *Group mobility*
    - *Mutual avoidance*: same as previous
    - *Velocity matching*: match velocity of group
    - *Group Centering*: head to center of group

$$\vec{a}_{\text{avoidWall}} = \gamma(\vec{pds}_i(t) - \vec{pds}_{w_i}(t))$$

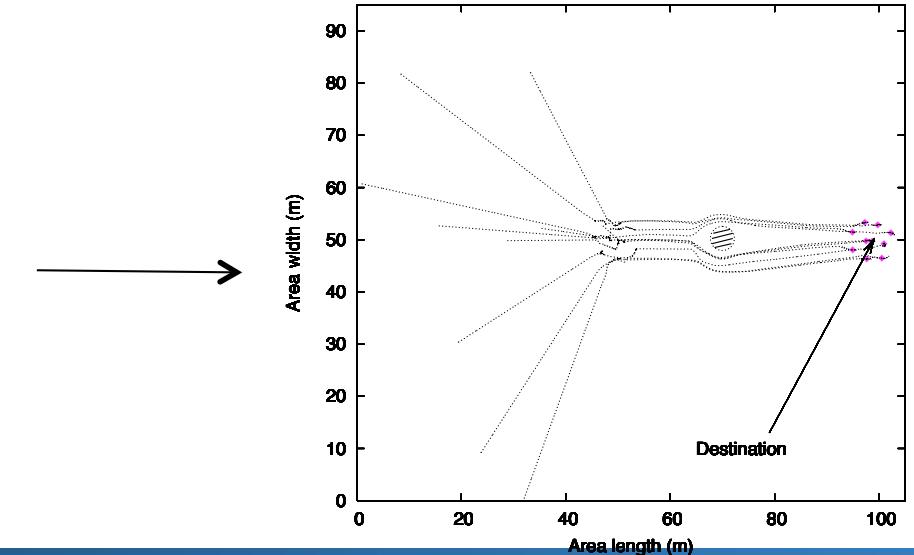
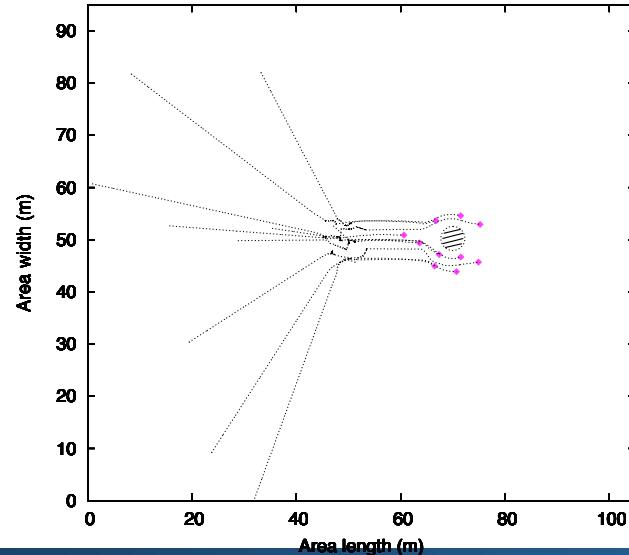
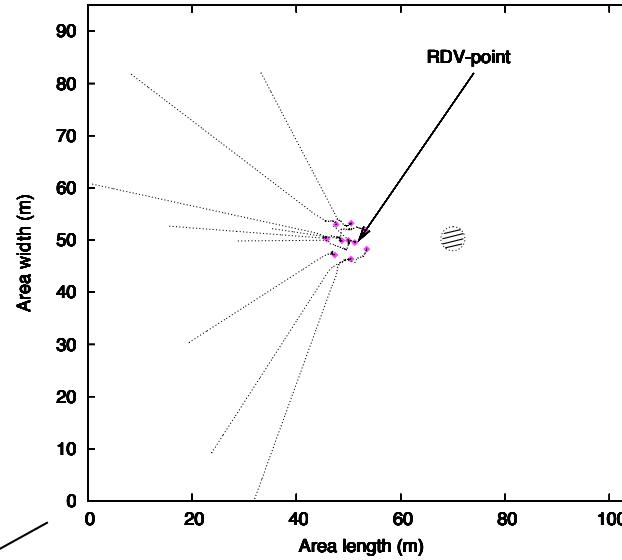
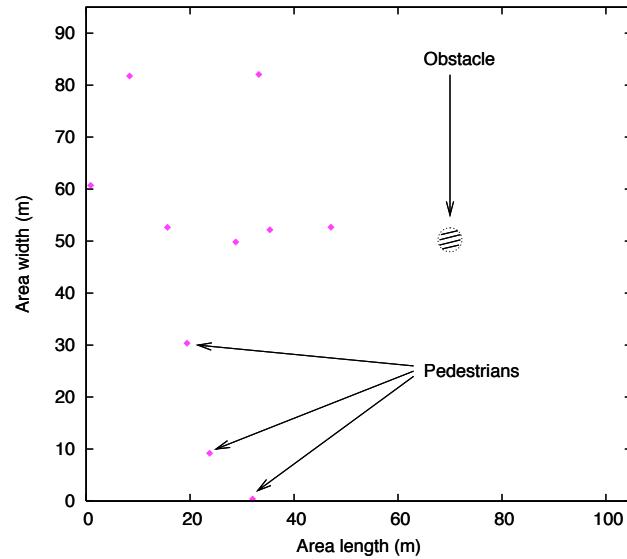
$$\vec{a}_{\text{avoidObstacle}} = \gamma(\vec{pds}_{S_i}(t) - \vec{pds}_i(t))$$

$$\vec{a}_{\text{mutualAvoidance}} = \sum_{j \in T_i(t)} \gamma(\vec{pdv}(x, t))$$

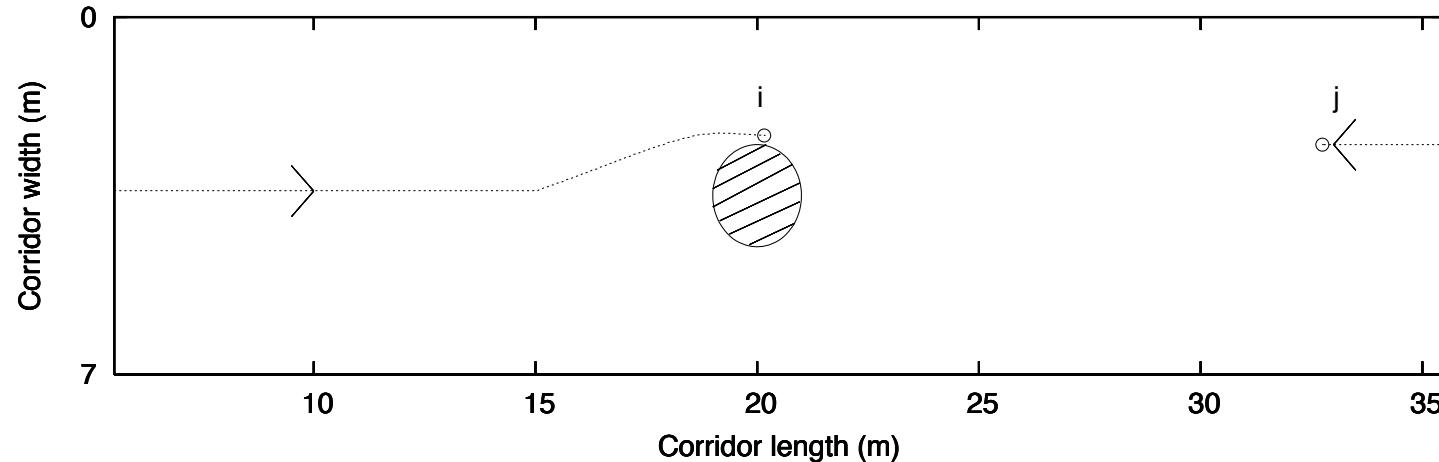
$$\vec{a}_{\text{VelocityMatching}} = \beta \left( \frac{1}{|N_G|} \sum_{x \in G} \vec{v}_x(t) \right) - \vec{v}_i(t)$$

$$\vec{a}_{\text{GroupCentering}} = \gamma \left( \frac{1}{|N_G|} \sum_{x \in G} \vec{pos}_x(t) \right) - \vec{pos}_i(t)$$

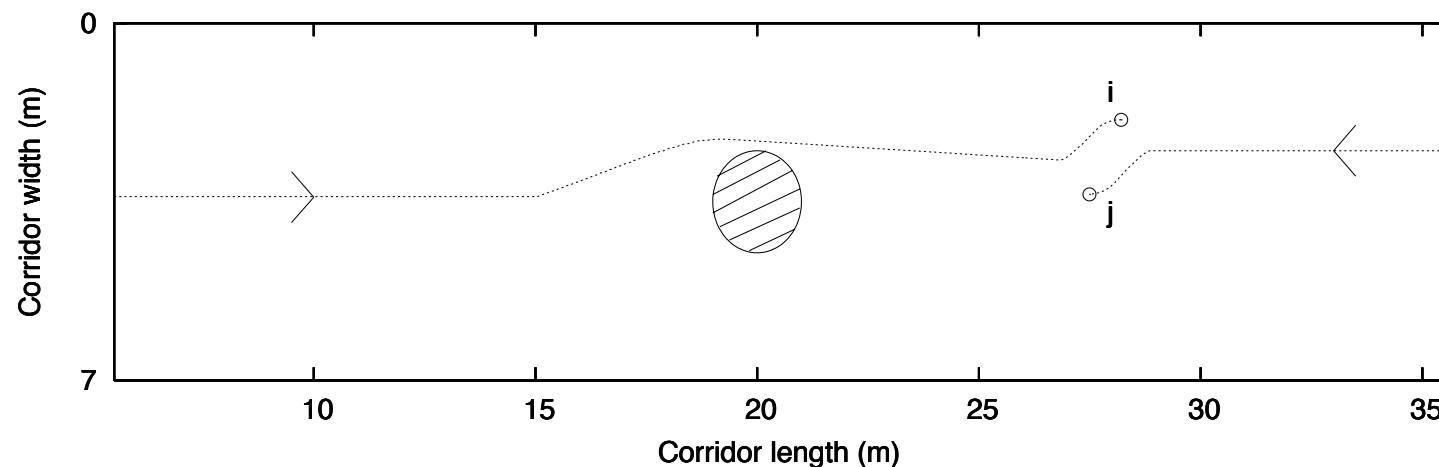
## More Realistic – Behavioral pedestrian motion



## More Realistic – Behavioral pedestrian motion (cont'd)



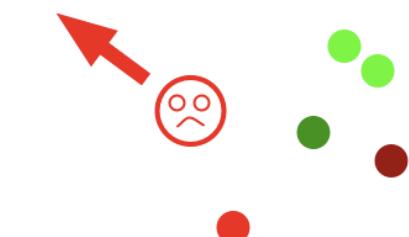
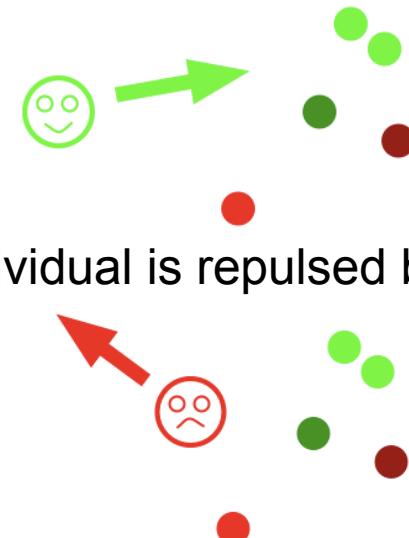
(a) At  $t=18$  s: obstacle avoidance of pedestrian i.



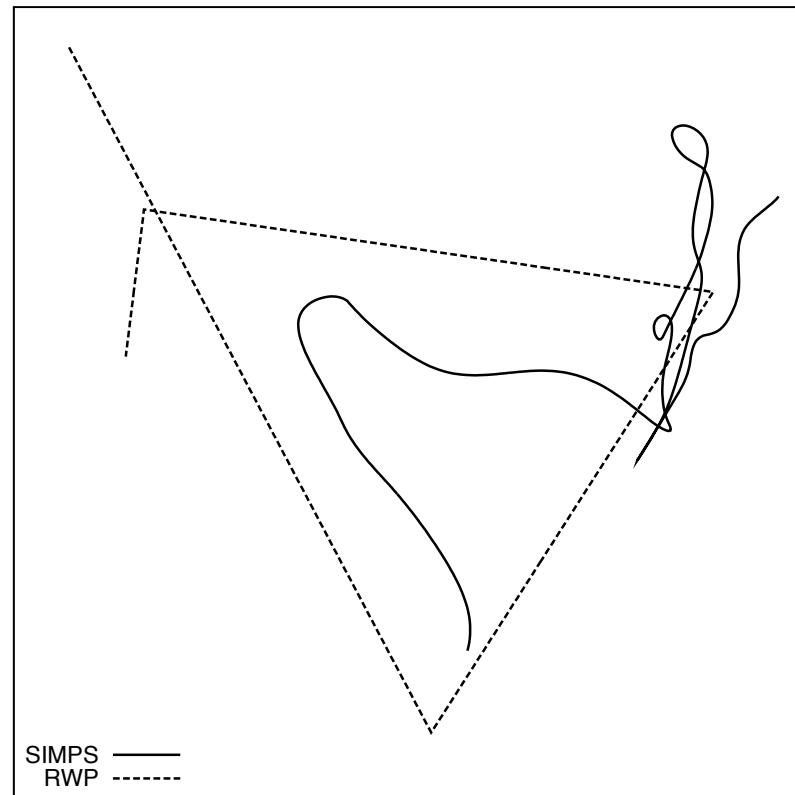
(b) At  $t=24.5$  s: mutual avoidance of pedestrians i and j.

## More Realistic – Social

- Aim at modeling the roots behind mobility [**Mascolo06**]
  - Human-beings are predominantly sociable
- Example of SIMPS [**Borrel08Simps**]
  - Translates *sociostation* in the mobility domain. Two behavioral rules:
    - **Socialize**: when under-socialized a an individual is attracted toward each of his acquaintances
    - **Isolate**: when over-socialized (bored), the individual is repulsed by each stranger



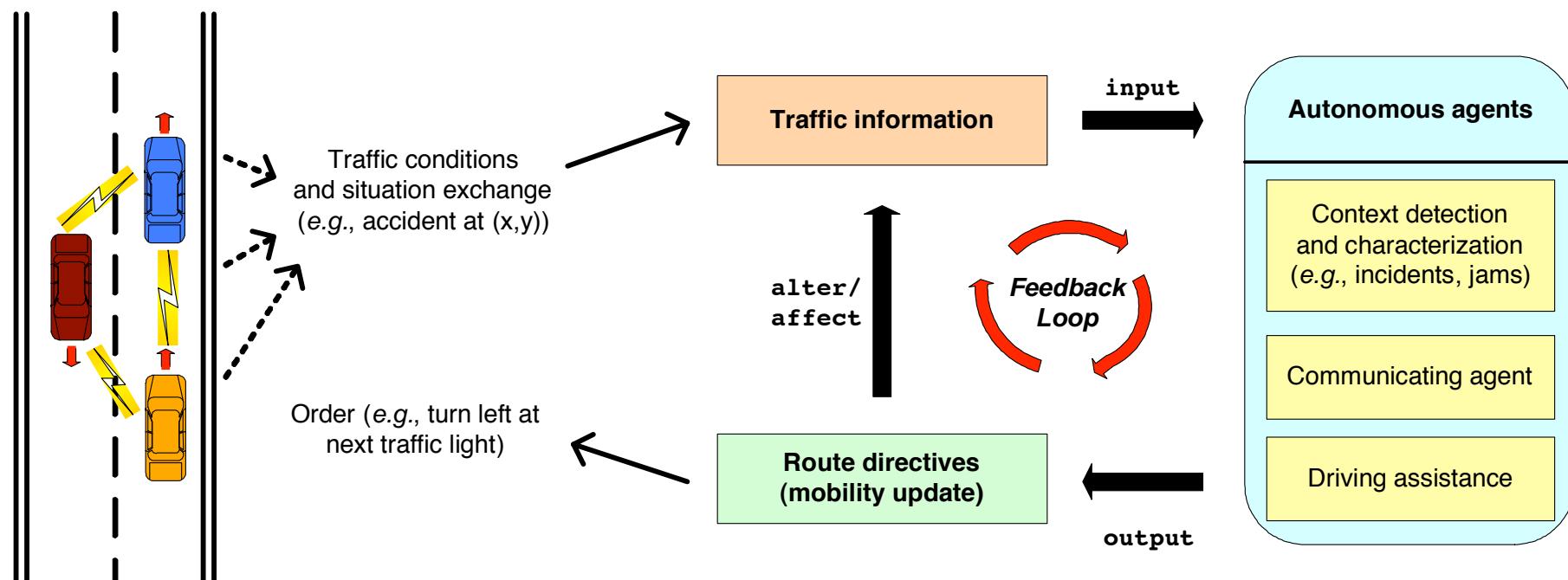
## More Realistic – Social



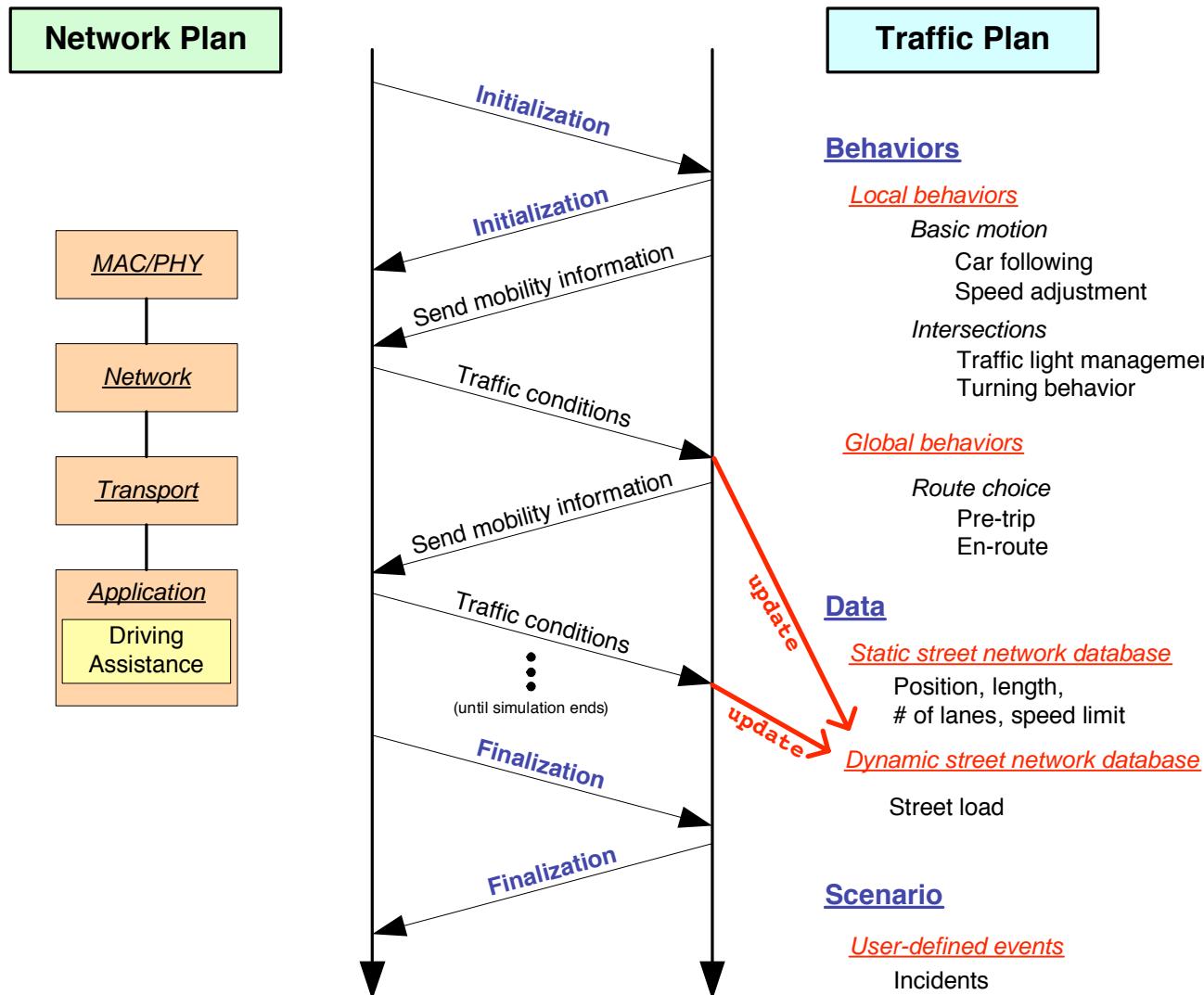
Comparative trajectories of RWP and SIMPS.

## More Realistic – Joint Simulations

- Binding a **network simulator** and **mobility generator** is required when a **feedback loop** exists
  - Mobility traces can no more be loaded at the start of the simulation



## More Realistic – Joint Simulations (cont'd)

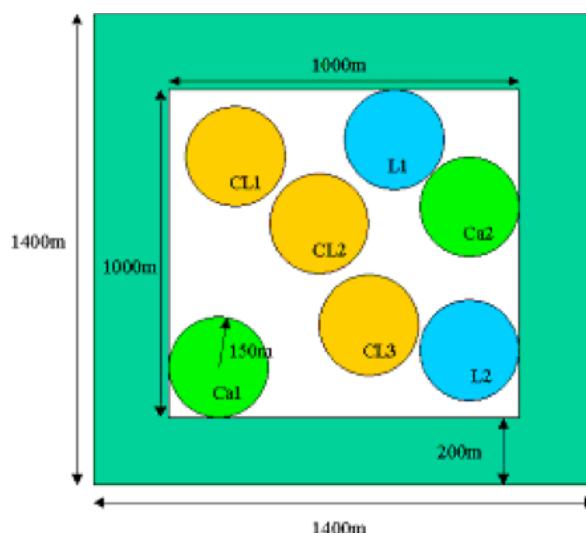


## More Realistic – Surveys and Trace-based

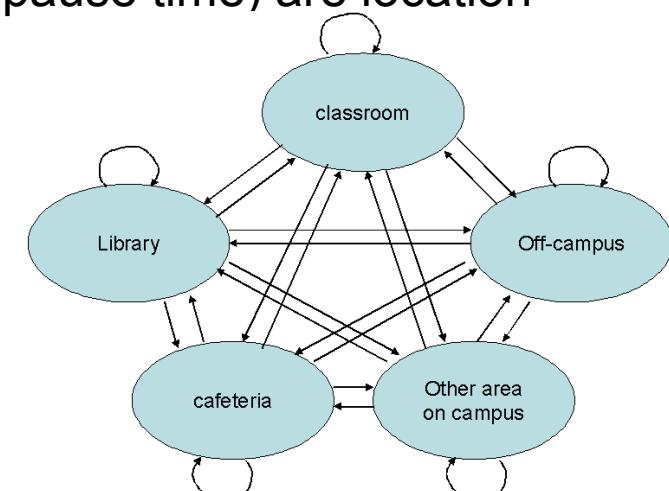
- Surveys
  - Observe or survey people
  - E.g.,
    - Brown with its microscope: Brownian motion (1827)
    - People overlooking pedestrians from top of buildings
- Trace-based models
  - Traffic sensors on roads
  - GPS recordings
    - Students on Campus [Dartmouth], Buses [Seattle], Taxis
  - Radio contacts (RFID, Bluetooth, Wifi) **[Crawdad]**
    - MIT, UCSD, Cambridge, ETH

## More Realistic – Surveys

- Weighted Waypoint **[Hsu05Weighted]**
  - Based on surveys from sampled respondents on USC campus during 4 weeks
  - Destinations are not randomly picked with the same weight across the simulation area
  - The parameters of a mobility model (e.g. pause time) are location-dependent and time-dependent



Map of virtual campus with categorized places:  
• CL=classroom  
• L=library  
• Ca=cafeteria



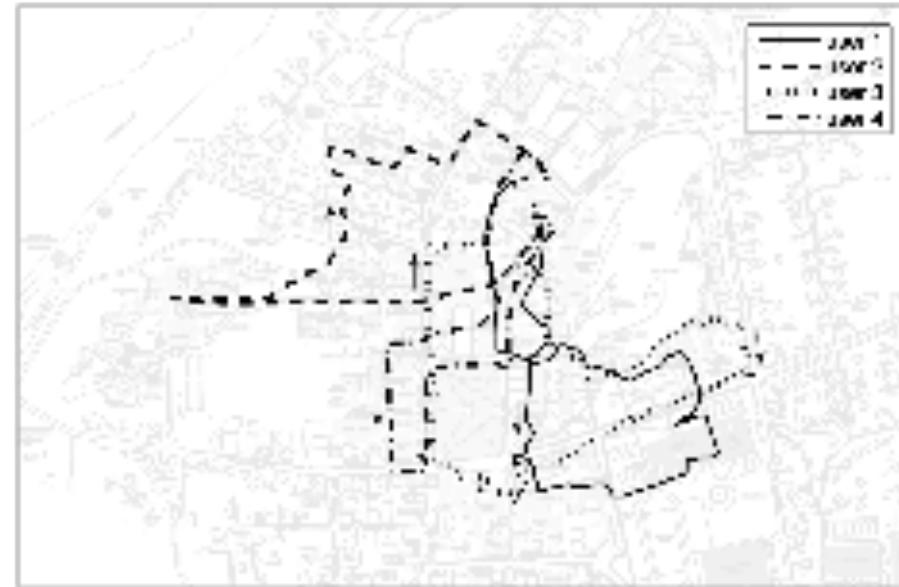
5-state Markov model with transitions between categorized places

## More Realistic - Traces

- Use of traces
  - Being **replayed** instead of using traces from a mobility model
  - Used to **calibrate** a model
    - Extract a mobility metric and try to match its distribution
  - Trace **analysis** (see next lectures on DTN)
    - Pluridisciplinary: time-series, graph theory, datamining

## More Realistic – GPS traces-based models

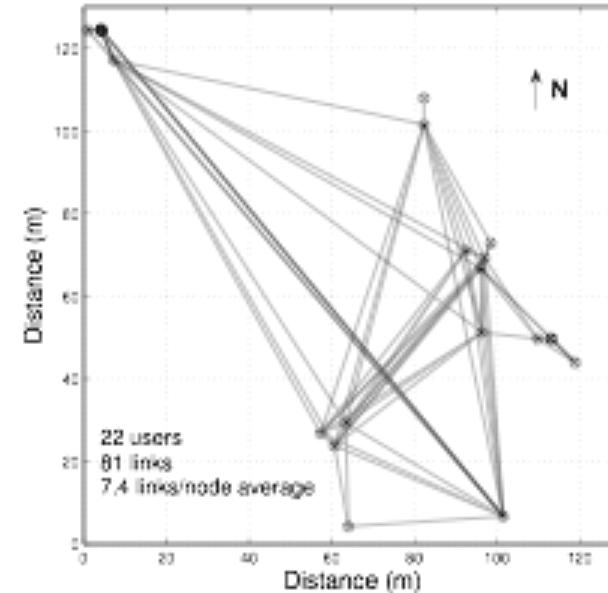
- Example of traces are Dartmouth campus **[Kim06Extracting]**
  - Student traced for several weeks with GPS-enabled devices



GPS tracks of four walks on Dartmouth campus

## More Realistic – Calibrated Campus Mobility Model

- Markovian model of AP cell displacements calibrated with ETH AP client associations **[Gross05Mobility]**
- Evolutionary topology model based on AP bindings **[McNett05Access]**
  - Extrapolation of user walk between AP



## Mobility Models – Complexity comparison

- Complexity of behavioral models
  - Search for neighboring entities and obstacles:  $O((n + o) \cdot \log(n + o))$ 
    - $n$  : number of mobile entities
    - $o$  : number of obstacles
  - Application of rules to each entity:  $O(m \cdot n)$ 
    - $m$  : number of rules combined simultaneously
  - Since  $(n + o) \gg m$  overall complexity is  $O((n + o) \cdot \log(n + o))$
- Complexity of synthetic models
  - $O(n \cdot m)$  (if implemented with a rule-based approach)
  - Eg., RWP can be modeled with two rules used alternatively,  $\{pause | moving\} \Rightarrow O(n)$

## Mobility Models – Complexity comparison (cont'd)

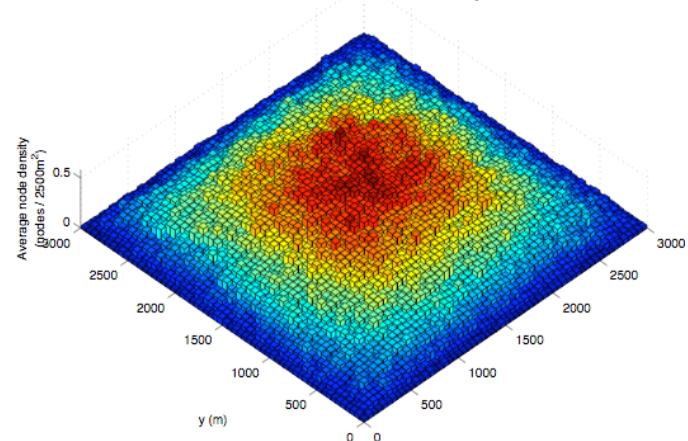
- Complexity of trace-replaying
  - $O(1)$
- Complexity of trace analysis
  - Can rapidly become  $NP$ -hard

## Mobility Models – Metric comparison

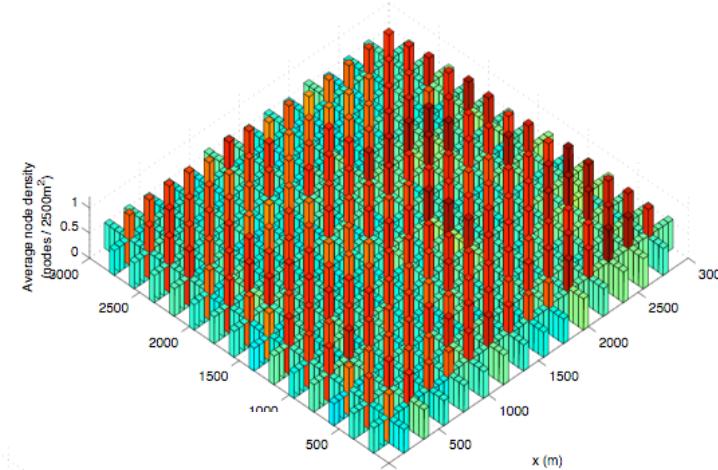
- Important Metrics [Bai03Important]
  - Node density
  - Relative movement direction
  - Number of Neighbors
  - Link lifetime (contact duration)
  - Network graph

# Mobility Models – Metric comparison

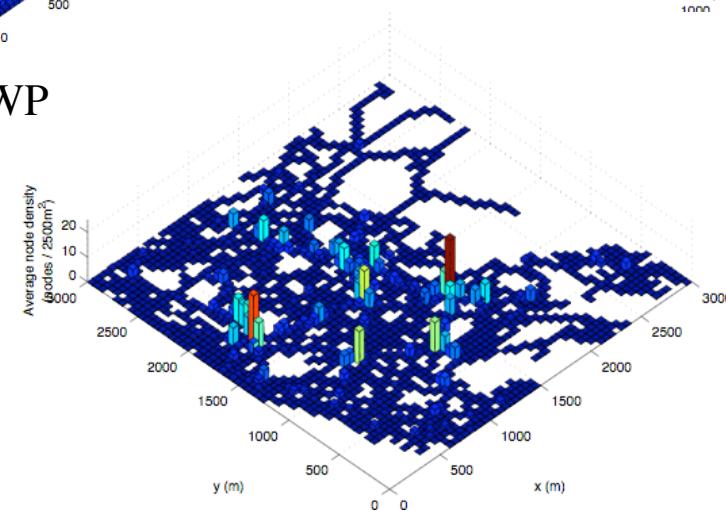
- Node Density



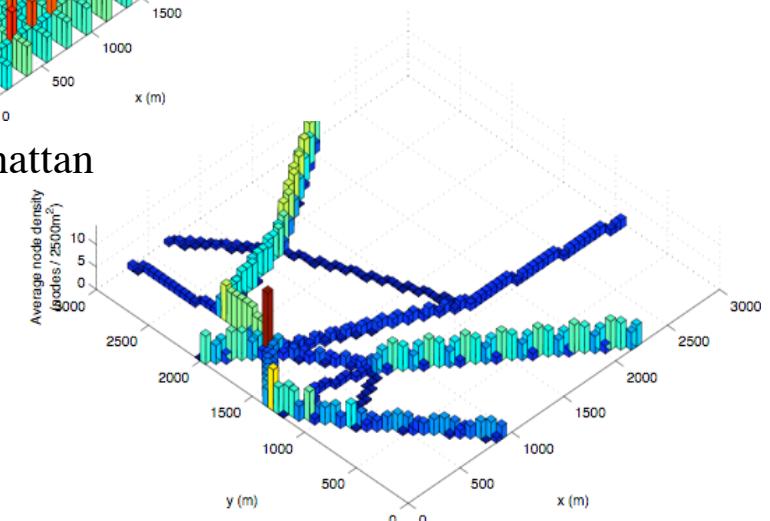
RWP



Manhattan

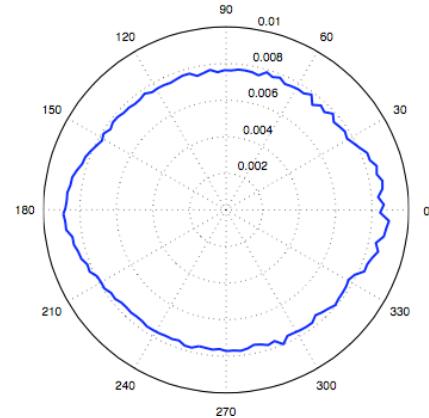


Vehicular BM

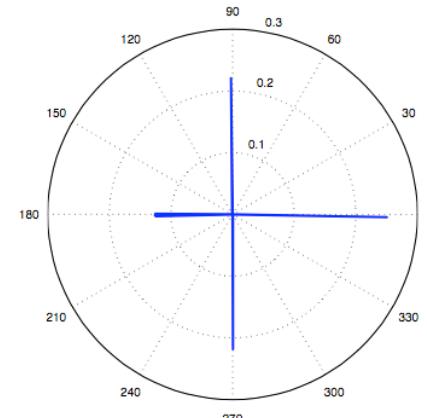
Vehicular traces  
(ETH ITS group)

# Mobility Models – Metric comparison

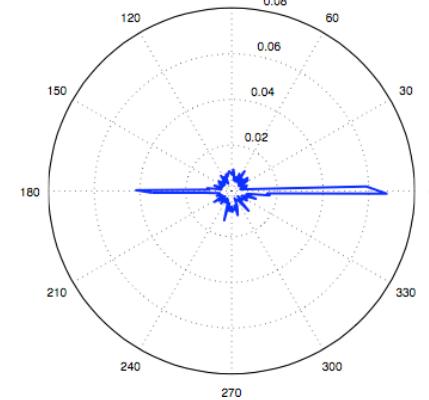
- Relative Movement Direction



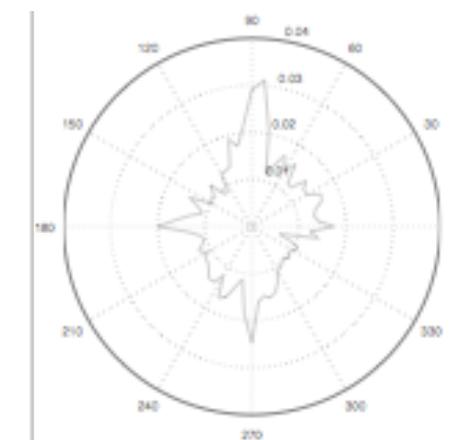
RWP



Manhattan

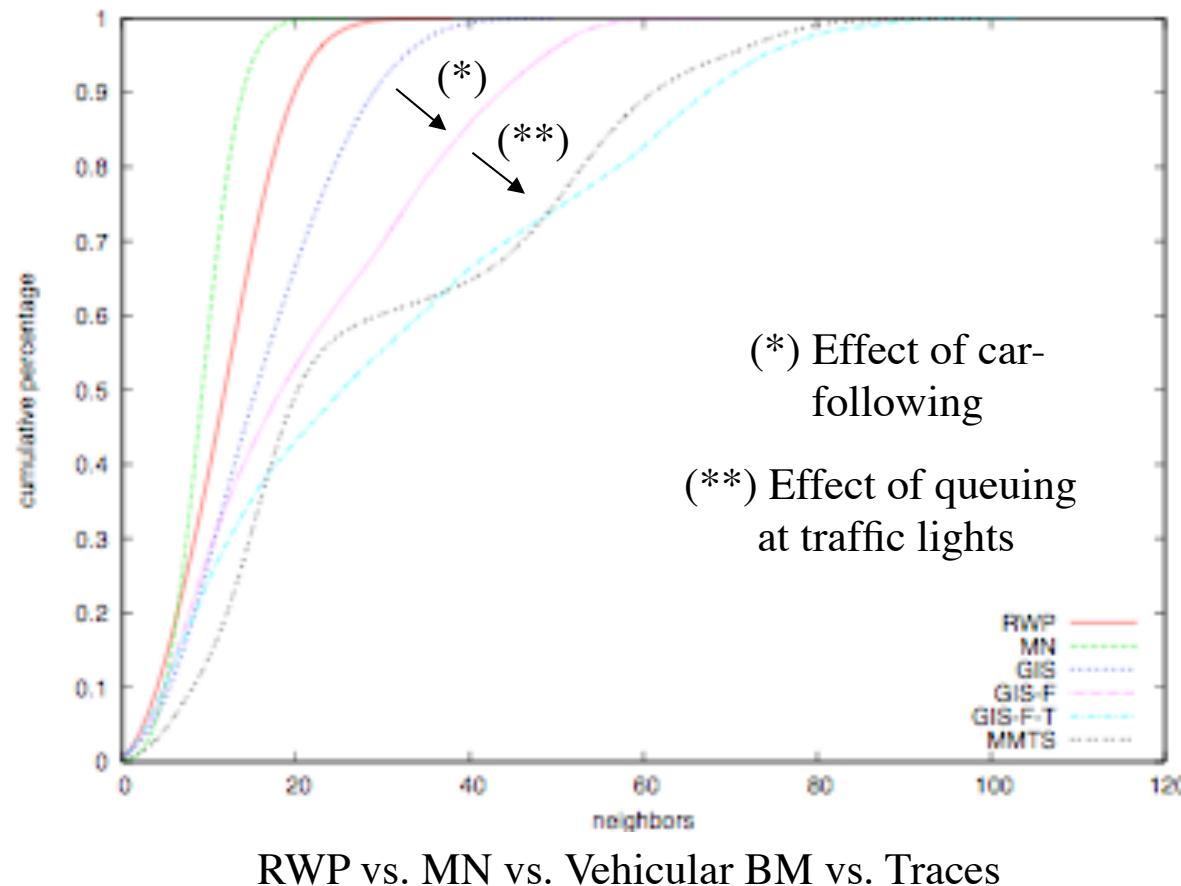


Vehicular BM

Vehicular traces  
(ETH ITS group)From GPS traces  
of students on  
Campus  
(Dartmouth)

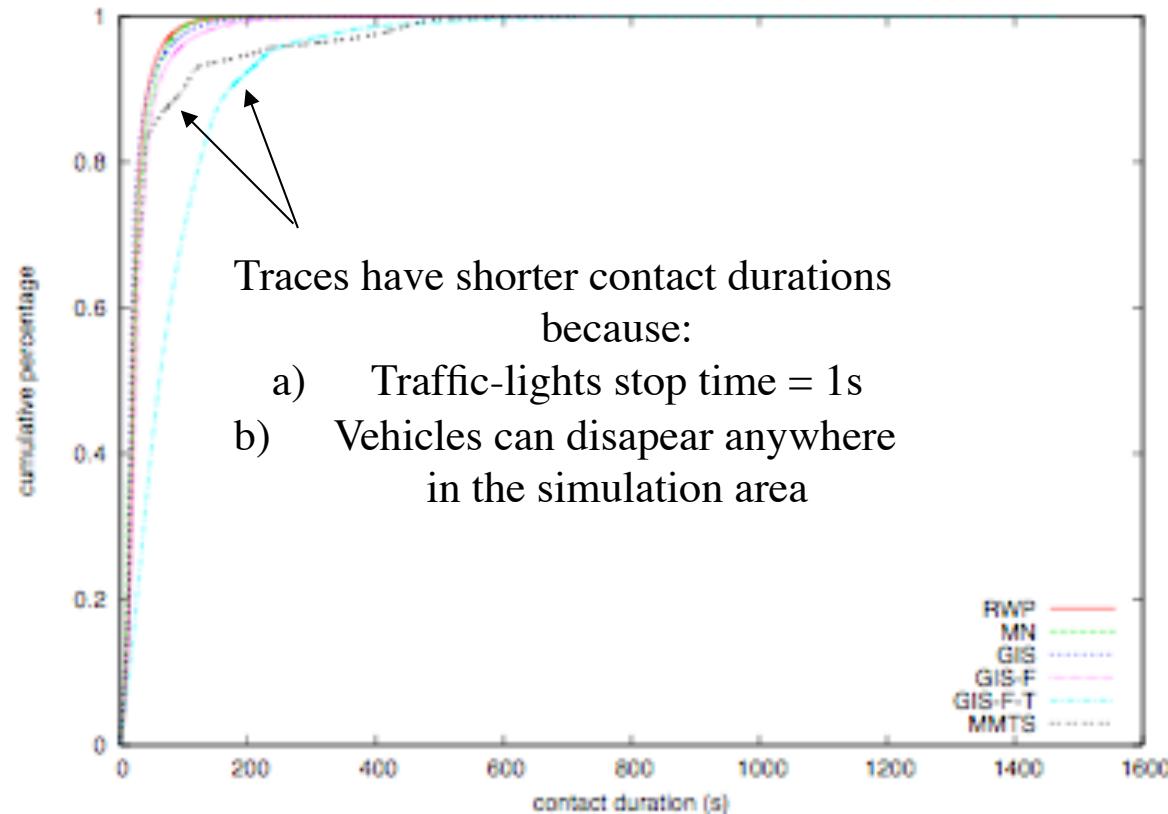
## Mobility Models – Metric comparison

- Node degree CDF



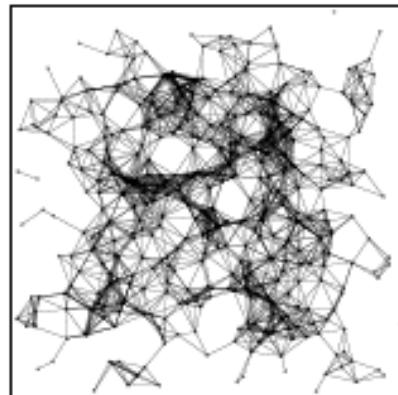
## Mobility Models – Metric comparison

- Contact duration CDF (link lifetime)

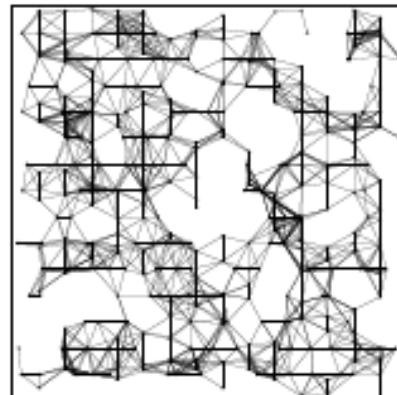


## Mobility Models – Metric comparison

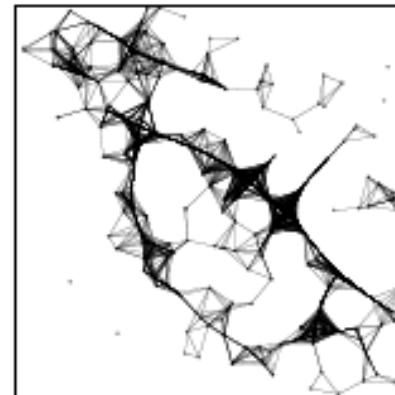
- Network Graph (snapshots)



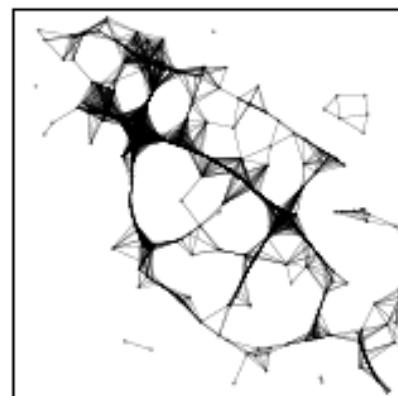
(a) Random Waypoint Model



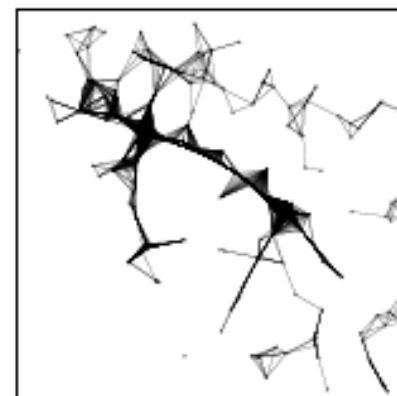
(b) Manhattan Model



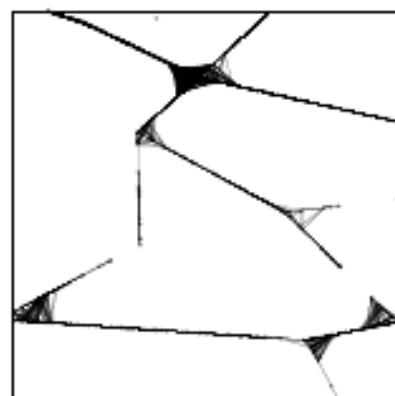
(c) GIS Model



(d) GIS Model with car-following



(e) GIS Model with car-following  
and traffic lights



(f) MMTS Model

# Mobility Models – Mobility generators and Frameworks

- Plenty of mobility generators
  - Pedestrians: GEMM [**Feeley04Realistic**]
  - Vehicles [**Choffnes05Traffic**, **CanuMobiSim**, **VanetMobiSim**]
  - Urban: Udel [**Kim05Survey**, **Kim05Realistic**], GMSF [**Baumann08GMSF**]
- As well as simulators
  - Ns-2 [**Ns2**]
  - Qualnet [**Qualnet**]
  - GloMoSim [**GlomoSim**]
  - Opnet [**Opnet**]
  - Omnet, ...

## Mobility Models - Conclusion

	Realistic	Tractable	Flexibility	Param. space	Comp. Complexity	Calibrated
Synthetic	+	Yes	++	Low	Low	Most not
Behavioral	++	No	++	High	High	Yes
Traces	++	/	-	/	Very Low	/

A good model is a tractable model (analytically)  
still representative of real-world mobility

It's a Tradeoff!

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# Outline

- Introduction
  - Rationale, Classification, State-of-art
- Mobility Models
  - From random to more realistic models
- Performance evaluation
  - Analytical vs. Simulations vs. Traces vs. Experiments
- System design
  - Designing better communication systems
- Outlook, demos and conclusion

# Performance Evaluation

- Introduction
- Performance Evaluation - Example of Content Dissemination
  - System formulation, derivation, and resolution
  - Experimentations

## Perf. Evaluation - Introduction

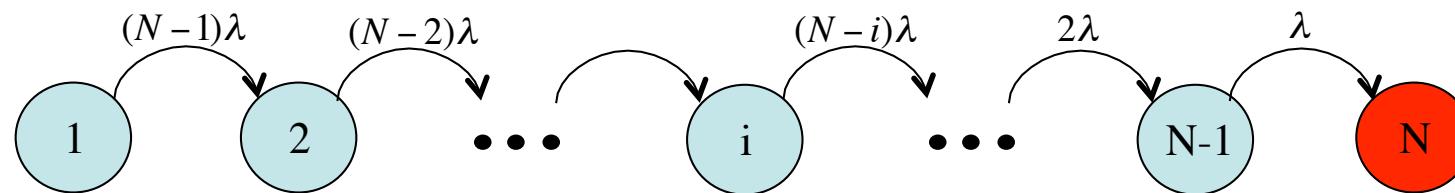
- So know that I'm a bit more acquainted with **mobility**, what can I do with it?
- **Evaluate your system!** (e.g., ad hoc routing protocol)
  - **How?**
    - 1) Analytically
    - 2) By simulation
    - 3) Trace-replaying
  - First, formalize your system with key parameters
    - Mobility-wise, what most impacts your system? E.g,
      - handoff in cellular networks
      - link-duration in ad hoc networks
      - inter-contacts in delay-tolerant applications

## Perf. Evaluation – Example of System to evaluate

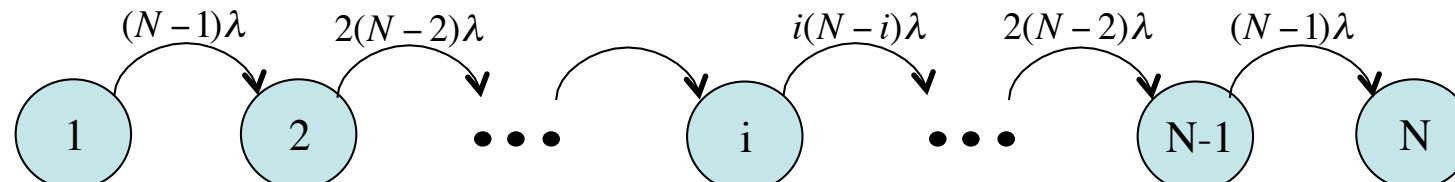
- Example of Content Dissemination
  - Consider a DTN network of  $N-1$  mobile nodes and an AP
  - Goal is to disseminate a given content to all nodes
  - Two strategies
    - *No cooperation*: content is provided only by AP
    - *Unlimited cooperation*: nodes store-and-forward content
  - Formalization – Key parameters
    - Number of nodes  $N$
    - Inter-contact rate  $\lambda$  (rate of inter-node encounters)
  - Performance evaluation
    - What is the **delay** until all nodes get the content?

## Perf. Evaluation – System formalization

- Example with Continuous Time Markov Chains (CTMC) **[Bremaud]**
  - Each state represents the number of nodes having content
  - Sequence of inter-contact times are *iid* and exponentially distributed
- No-cooperation strategy



- Unlimited cooperation



## Perf. Evaluation – System derivation

- Overall delivery time  $E[T_{odt}]$  = time to absorption (state N)
- No-cooperation strategy

$$E[T_{odt}] = \sum_{i=1}^{N-1} \frac{1}{\lambda_i} = \frac{1}{\lambda} \sum_{i=1}^{N-1} \frac{1}{N-i} = \frac{1}{\lambda} \sum_{j=1}^{N-1} \frac{1}{j} = \frac{1}{\lambda} H_{N-1}$$

$$\Leftrightarrow E[T_{odt}] = \frac{1}{\lambda} \left( \gamma + \ln(N-1) + O\left(\frac{1}{N-1}\right) \right)$$

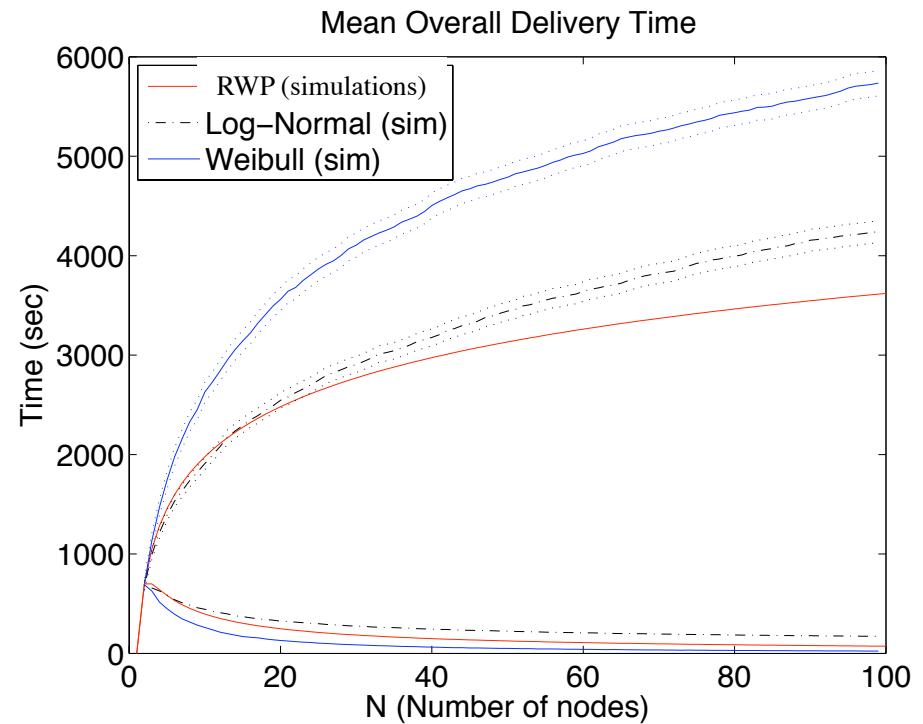
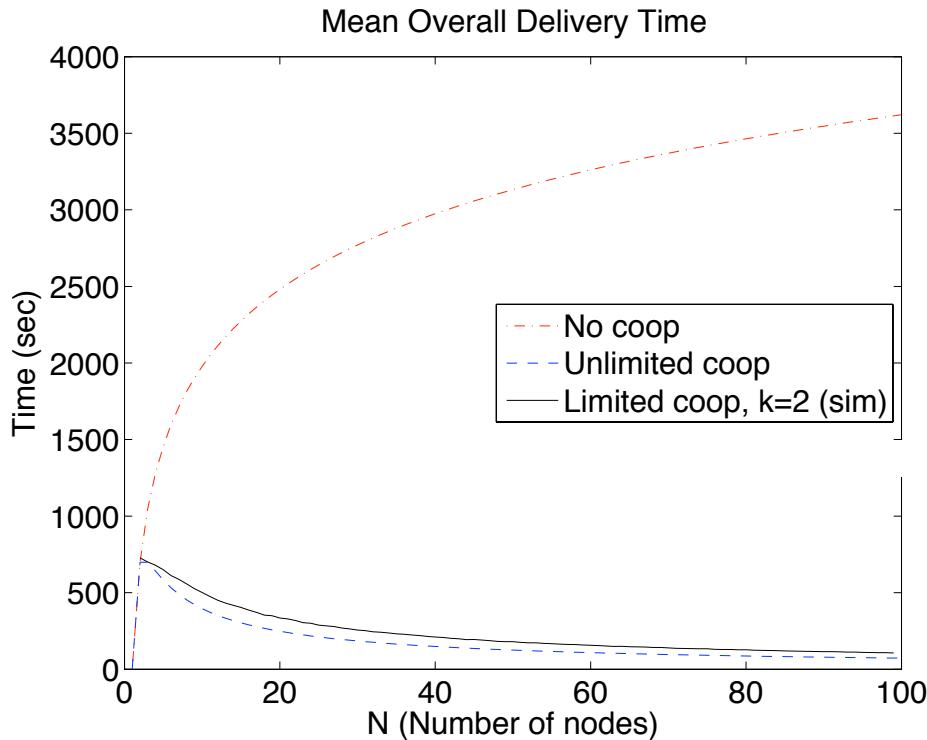
- Unlimited cooperation

$$E[T_{odt}] = \frac{2}{\lambda N} \left( \gamma + \ln(N-1) + O\left(\frac{1}{N-1}\right) \right)$$

- Note
  - More complex strategies have non closed-form expressions (e.g., 3D CTMC) and requires to resort to numerical evaluation

## Perf. Evaluation – System resolution

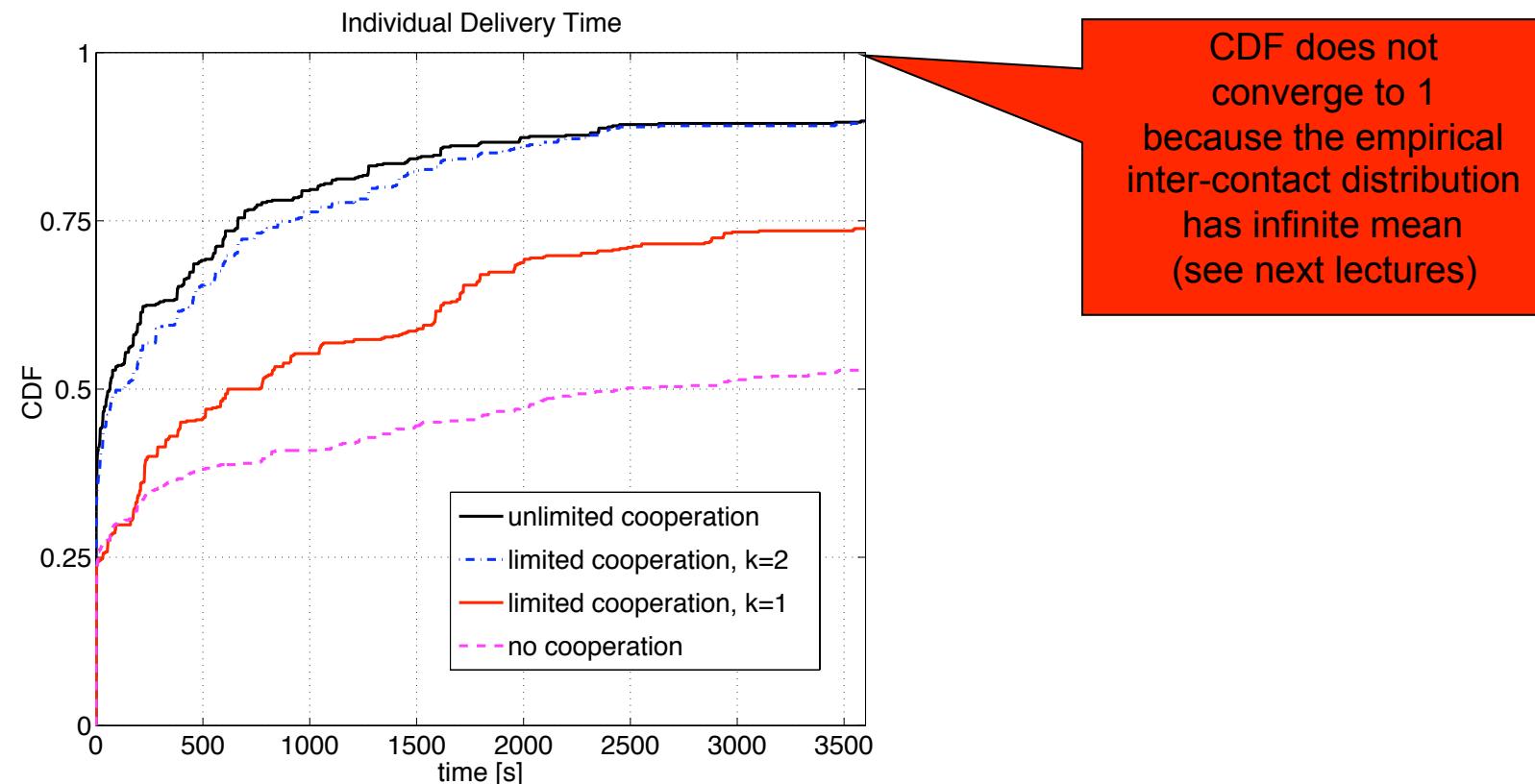
- Numerical evaluation of closed-form equations (l.) vs. simulations (r.)



- Simulations with RWP (left red) confirms the relevance of our model
- Simulations with other inter-contact distributions confirms the qualitative behavior of our model

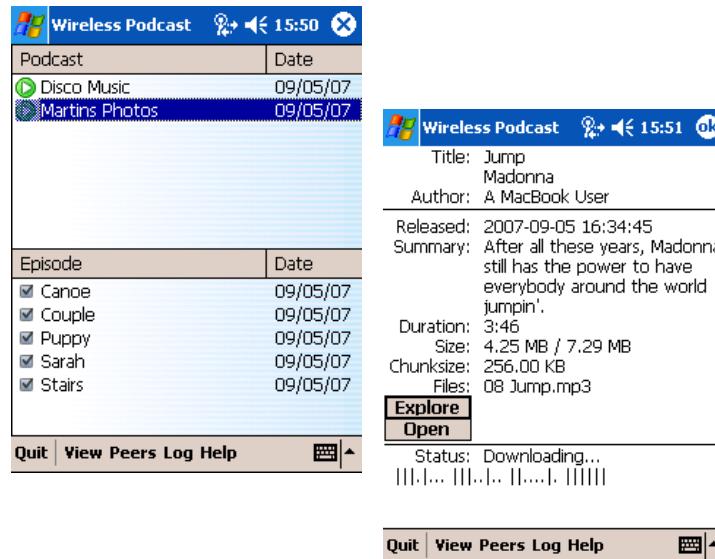
## Perf. Evaluation – System resolution with traces

- Replaying traces also confirms the analytical results (black vs. pink)



## Perf. Evaluation – System experimentation

- Don't have results from content dissemination experiment yet (soon)
- But be aware that
  - Home-made simulator required **2 days** of code development
  - Trace collection at ETH CSG required **2 months** (SA)
  - Software development required **6 months** for having first prototype! (MA)



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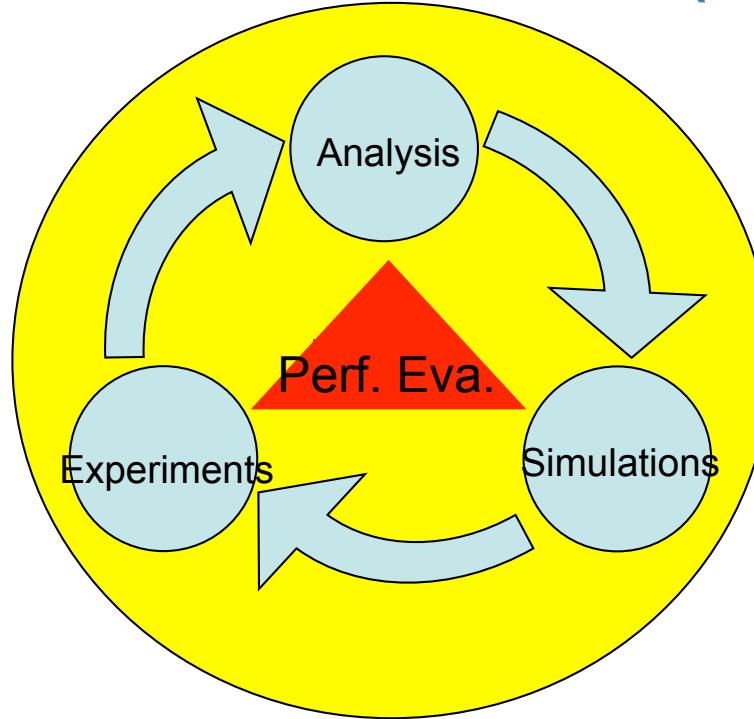
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## Performance Evaluation – Conclusion (cont'd)



A good researcher should carry **analytical performance evaluation**, **simulations**, and possibly **real-world experiments**.

## Papers you should definitely read

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- **[Kim06Extracting]** Minkyong Kim, David Kotz, and Songkuk Kim, “**Extracting a mobility model from real user traces**,” IEEE Infocom 2006

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# Questions? Discussion ...

