

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

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5. *Über die von der molekularkinetischen Theorie der Wärme geforderte Bewegung von in ruhenden Flüssigkeiten suspendierten Teilchen;*
von A. Einstein.

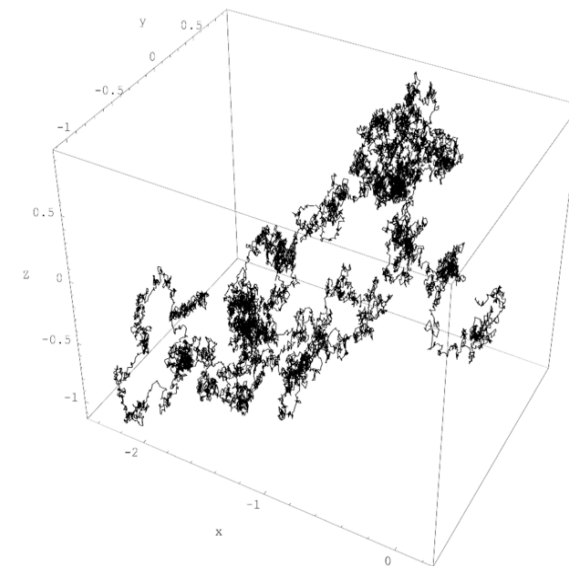
In dieser Arbeit soll gezeigt werden, daß nach der molekularkinetischen Theorie der Wärme in Flüssigkeiten suspendierte Körper von mikroskopisch sichtbarer Größe infolge der Molekularbewegung der Wärme Bewegungen von solcher Größe ausführen müssen, daß diese Bewegungen leicht mit dem Mikroskop nachgewiesen werden können. Es ist möglich, daß die hier zu behandelnden Bewegungen mit der sogenannten „Brownschen Molekularbewegung“ identisch sind; die mir erreichbaren Angaben über letztere sind jedoch so ungenau, daß ich mir hierüber kein Urteil bilden konnte.

Wenn sich die hier zu behandelnde Bewegung samt den für sie zu erwartenden Gesetzmäßigkeiten wirklich beobachten läßt, so ist die klassische Thermodynamik schon für mikroskopisch unterscheidbare Räume nicht mehr als genau gültig anzusehen und es ist dann eine exakte Bestimmung der wahren Atomgröße möglich. Erwies sich umgekehrt die Voraussage dieser Bewegung als unzutreffend, so wäre damit ein schwerwiegendes Argument gegen die molekularkinetische Auffassung der Wärme gegeben.

§ 1. Über den suspendierten Teilchen zuzuschreibenden osmotischen Druck.

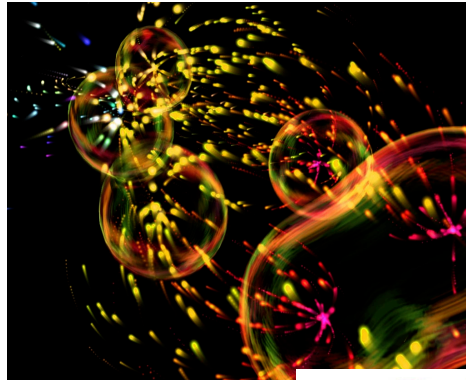
Im Teilvolumen V^* einer Flüssigkeit vom Gesamtvolumen V seien z -Gramm-Moleküle eines Nichtelektrolyten gelöst. Ist das Volumen V^* durch eine für das Lösungsmittel, nicht aber für die gelöste Substanz durchlässige Wand vom reinen Lösungs-

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



Many domains

Physics



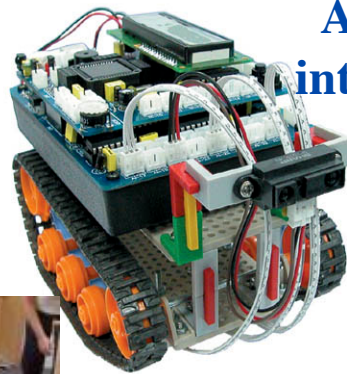
Transportation systems



Biology



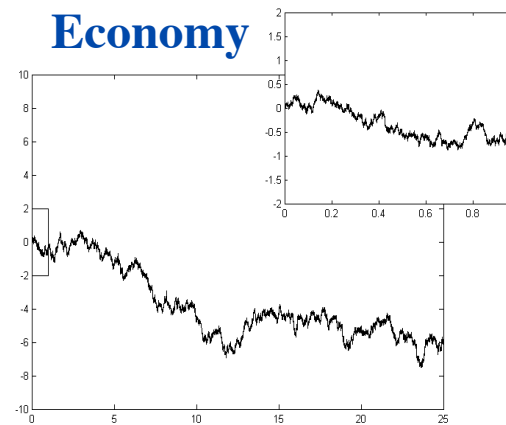
Artificial intelligence



Architecture

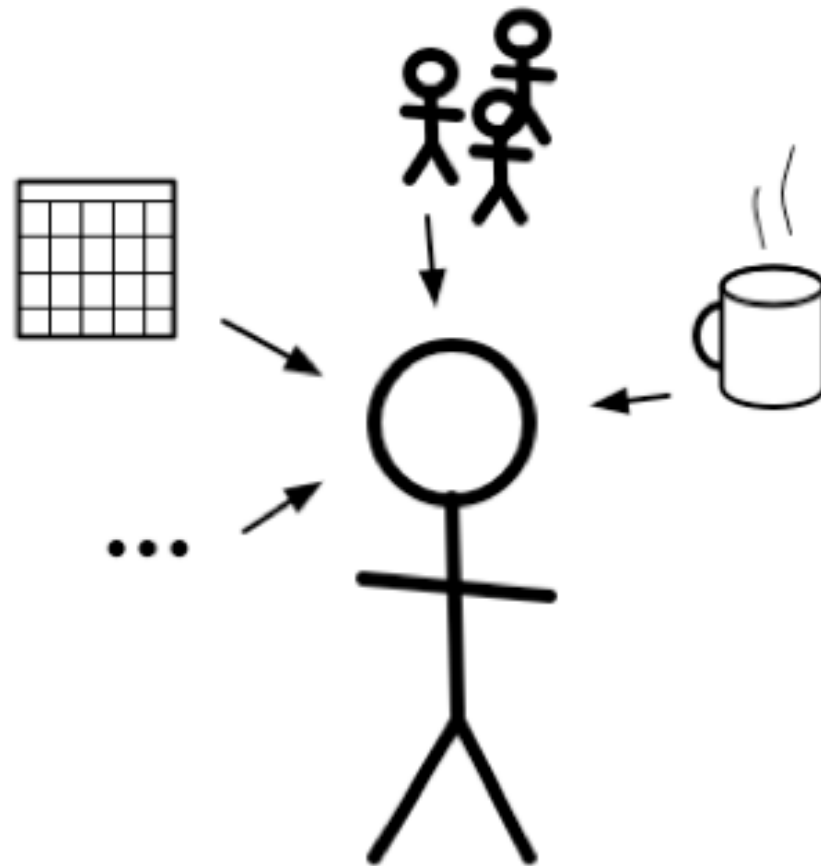


Economy



Gaming

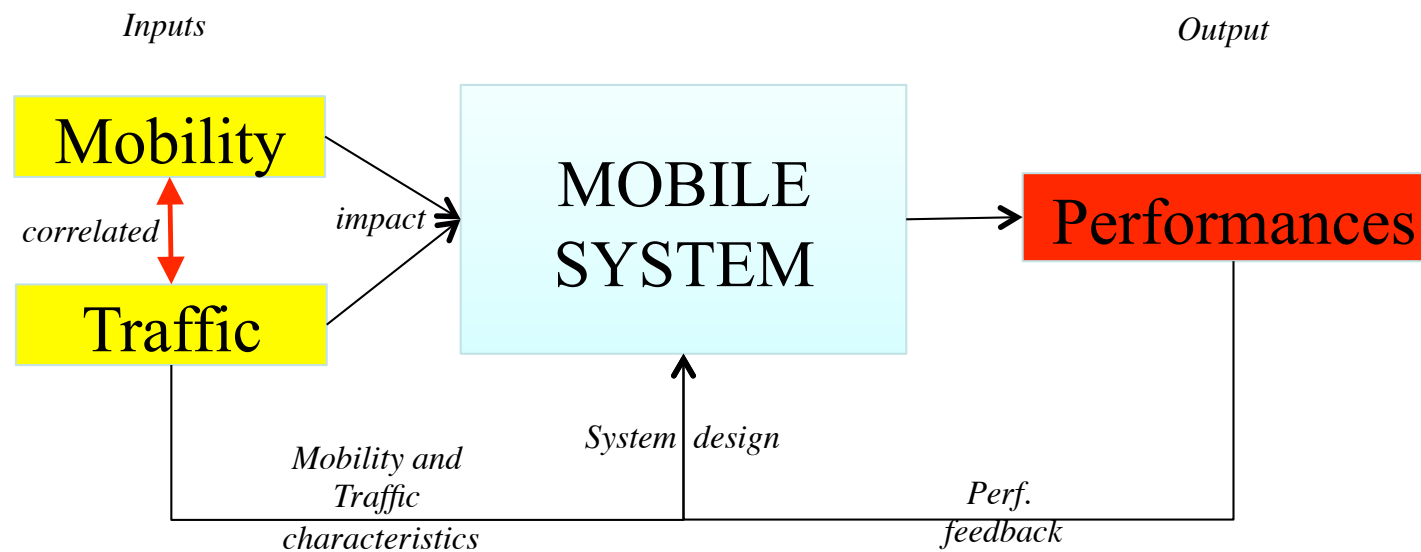
Understanding mobility is complex



Rationale for Mobility Models

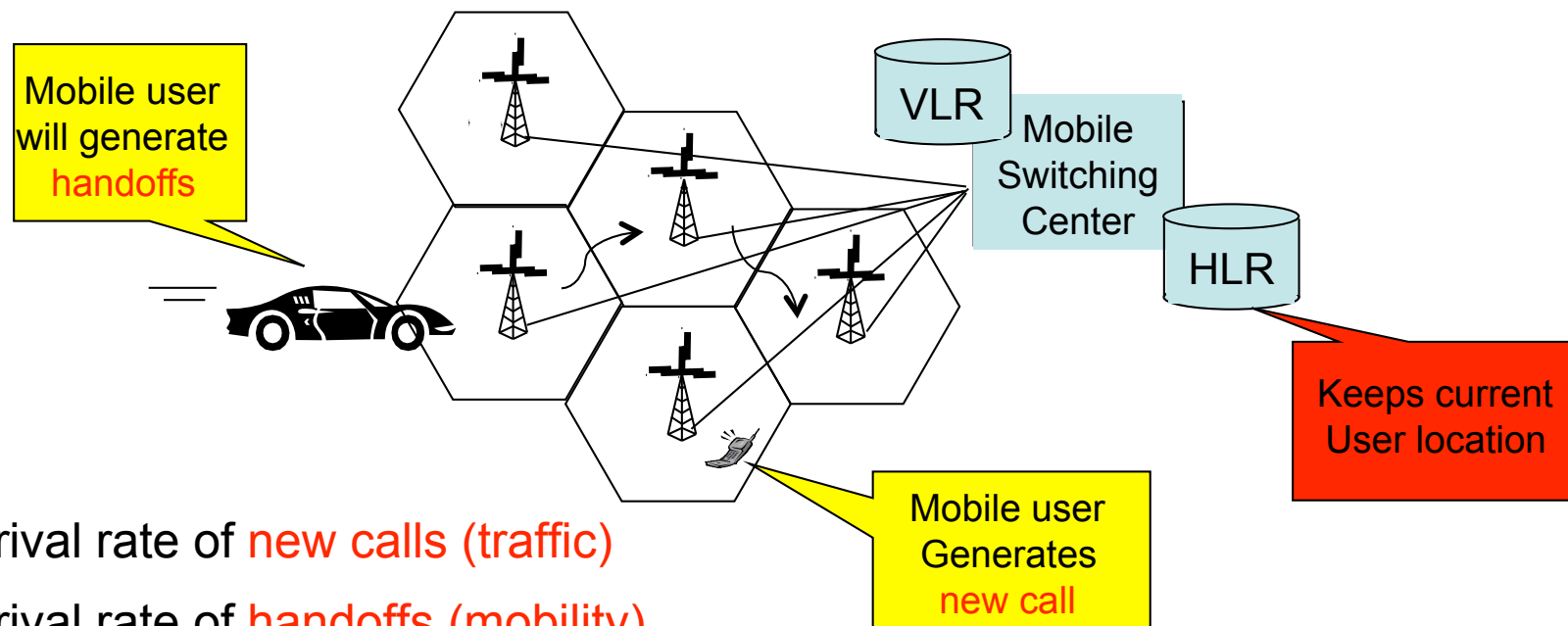
- Mobility Models are required for
 - Performance evaluation
 - Analytical
 - A system dynamics must be tractable in order to derive characteristics of interest
 - Simulations
 - Often used as an alternative when models are too complex (no analytical derivation)
 - But still complementary to the analytical 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

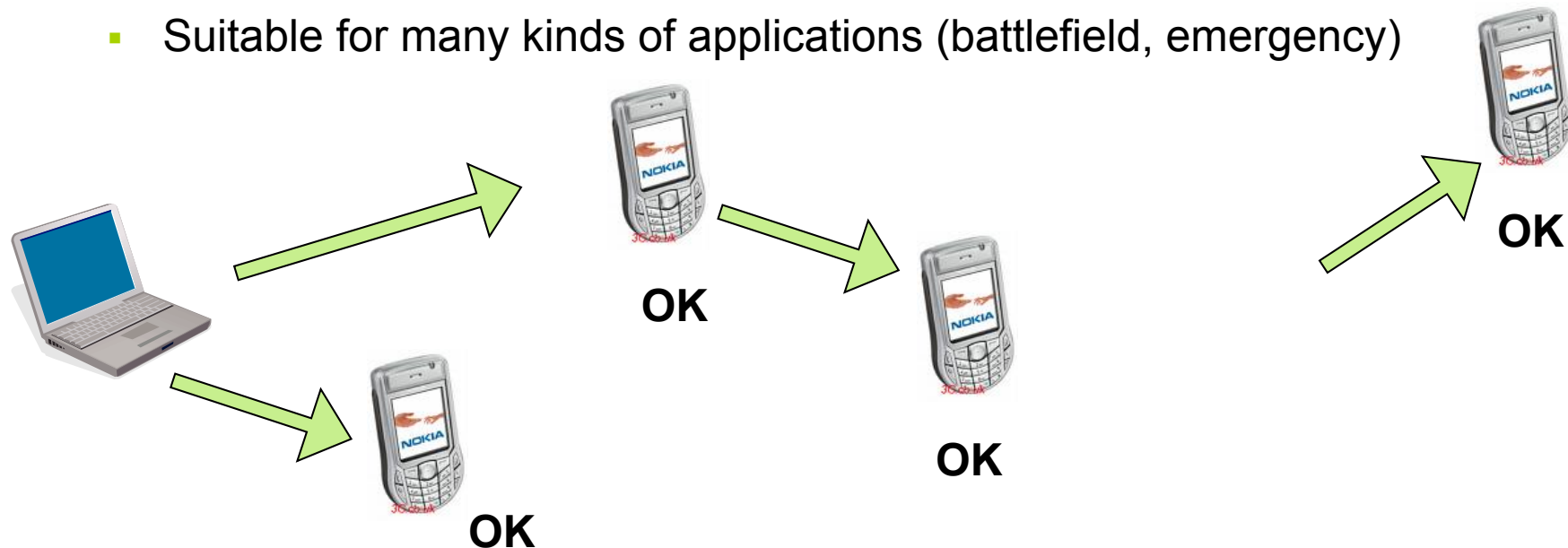
- Aim at providing integrated communications (i.e., voice, video, and data) between nomadic subscribers in a seamless fashion



- 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?

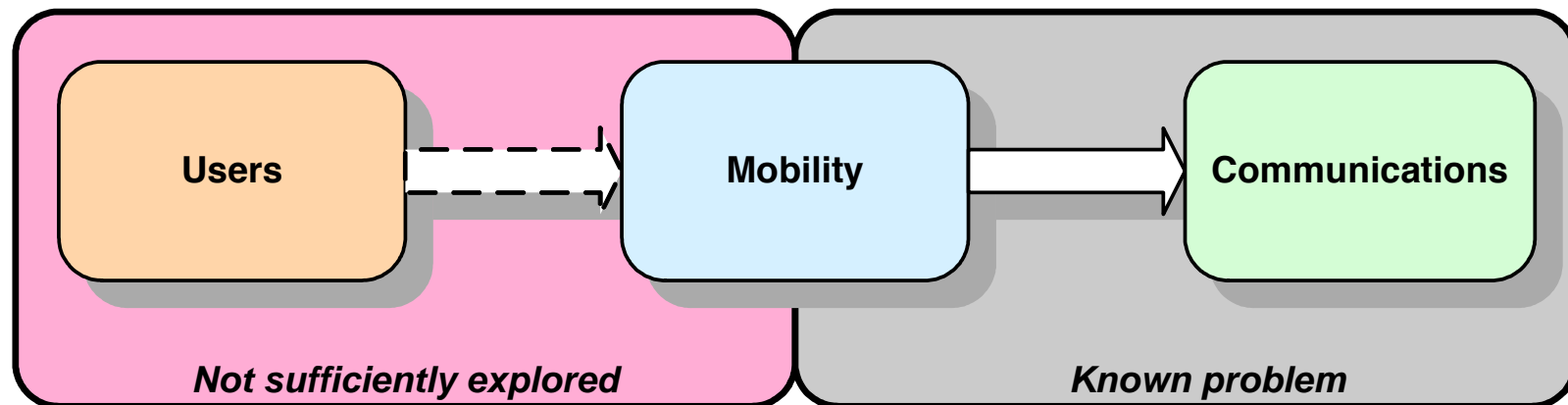
Classification of Mobility Models

- 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, RPGM City Section	<i>More Realistic:</i> Campus, Vehicular	Smooth RWP, Behavioral

The current situation in networking



Courtesy of Prof. Ammar

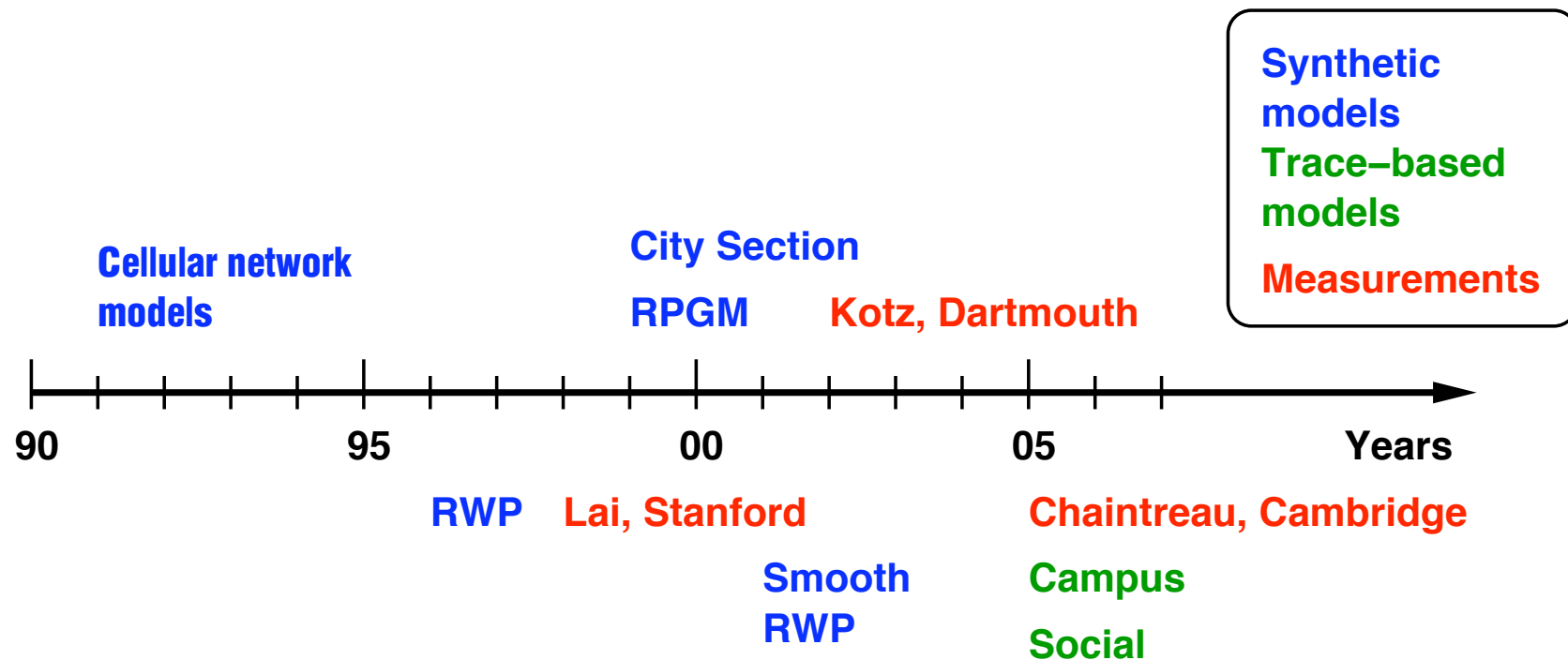
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Mobility Models – From Random to more Realistic

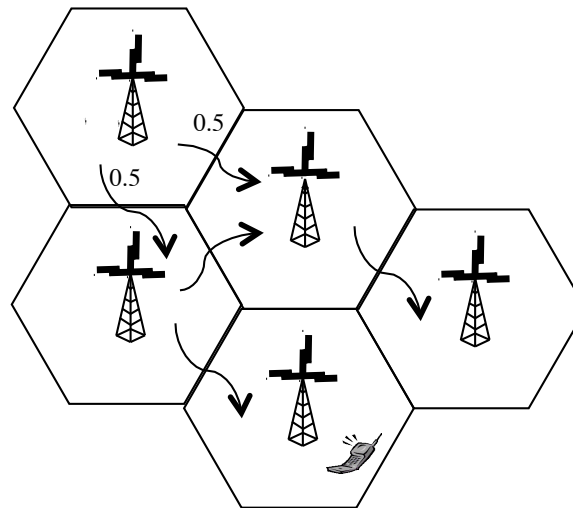
- Cellular models
- Random Mobility models (synthetic) [**Camp02Survey**]
 - Ad Hoc
 - Vehicular
- More realistic mobility models
 - Extension of random models
 - Behavioral models: Ad Hoc, Vehicular [**Haerri06Survey**], Social
 - Survey and Trace-based models

Mobility Models – Review



Cellular model – Markovian

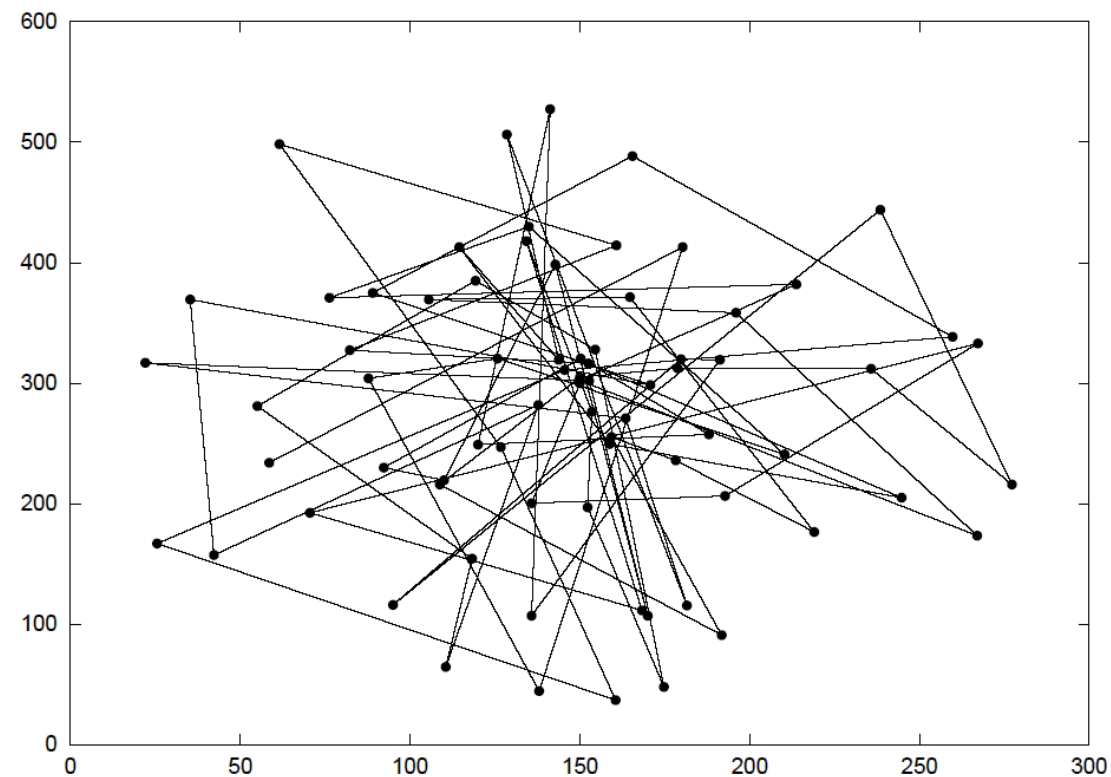
- Each transition from a cell i to j has a defined probability



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)

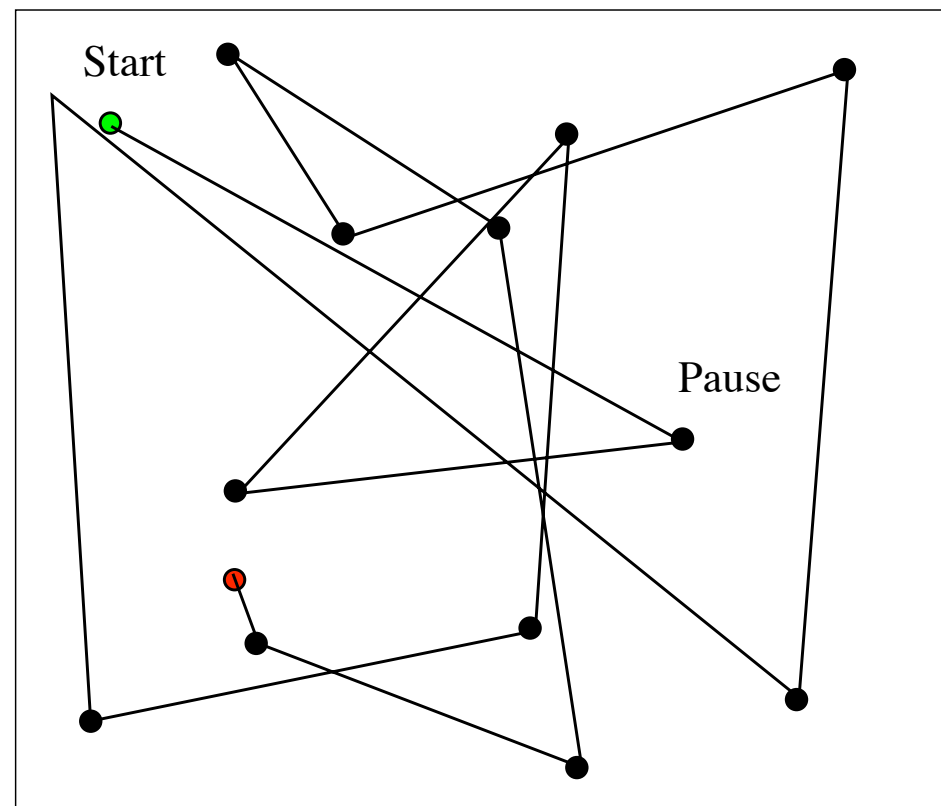


Trajectory of one MN under Random Walk

Synthetic model – Random Waypoint (RWP)

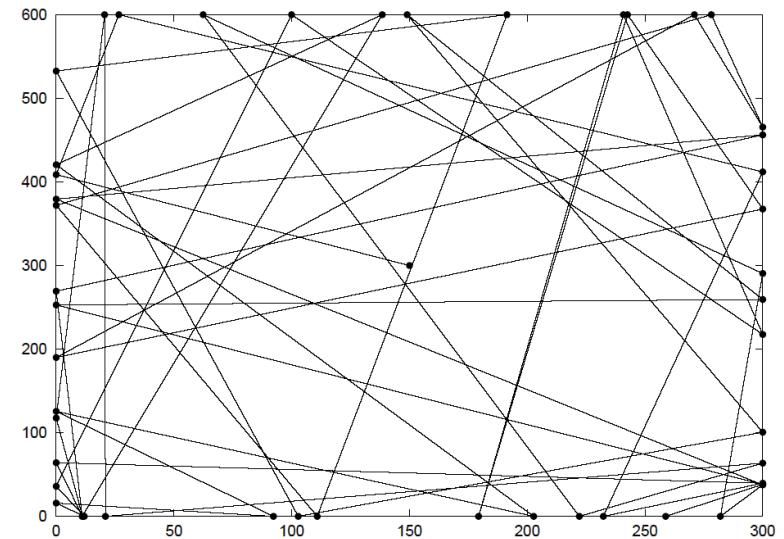
- An MN begins by staying in one location for a certain period of time (i.e., a pause time)
- Once this time expires, the MN chooses a random destination in the simulation area and a speed that is uniformly distributed between $[minspeed, maxspeed]$
- The MN then travels toward the newly chosen destination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

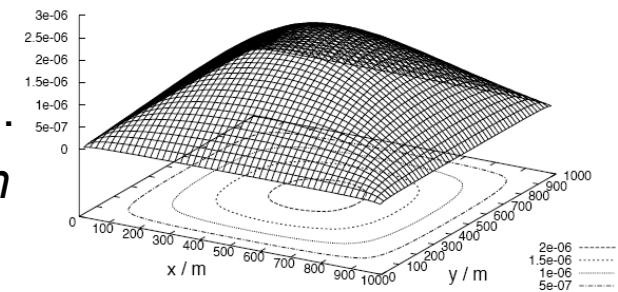
■ The case of RWP [Bettstetter02Spatial]

- 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

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

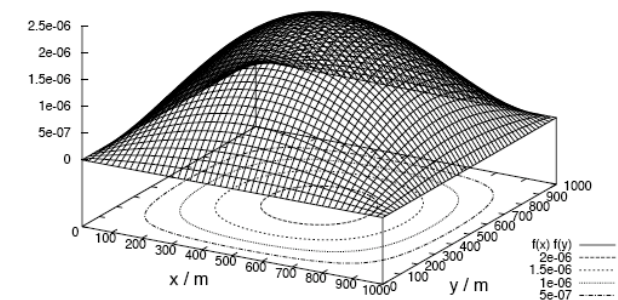
- Assuming a 2D RWP movement in a square area consisting of two independent one-dimensional movement processes along the x and y axes, we have:

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



a. Square simulation area

Simulations (up) vs.
analytic (down)



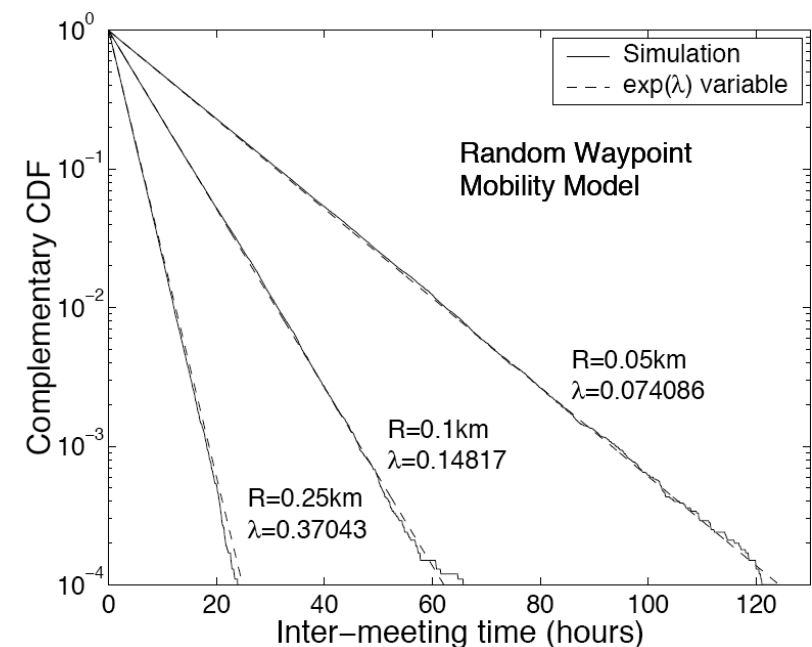
a. Square simulation area: $f(x)f(y)$

Mobility Models – Analytical derivation

■ The case of RWP and Random Direction [**Groenvelt05Message**]

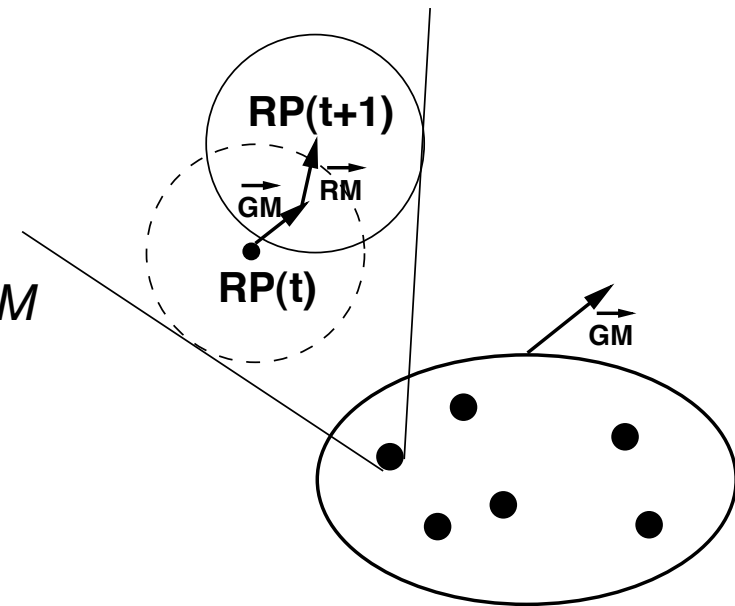
- The inter-contact rate is approximated by
$$\lambda \approx \frac{2 \omega r E[V^*]}{L^2}$$
 - ω is a constant specific to the mobility model
 - $\omega = 1.3683$ for RWP
 - $\omega = 1$ for RD
 - r communication range
 - $E[V^*]$ is the average relative speed between two nodes
 - L length of square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

- See also [**Sharma04Scaling**]

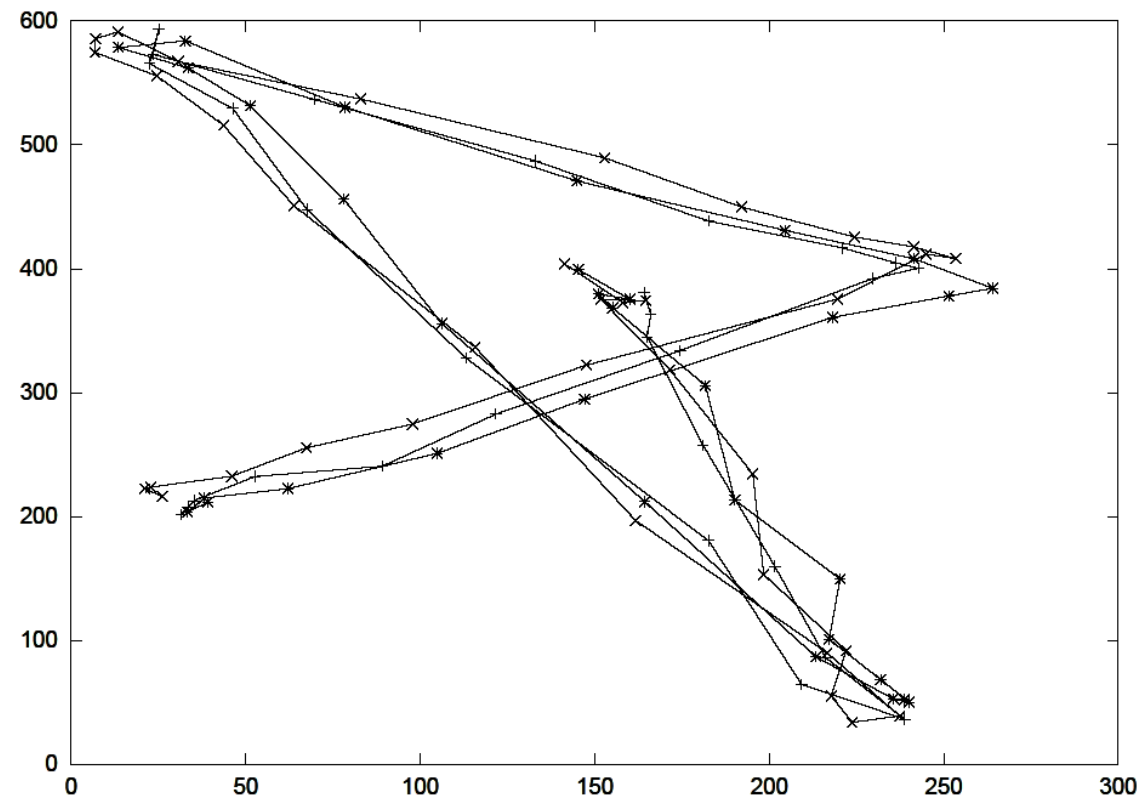


Synthetic model – Reference Point Group Mobility

- 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



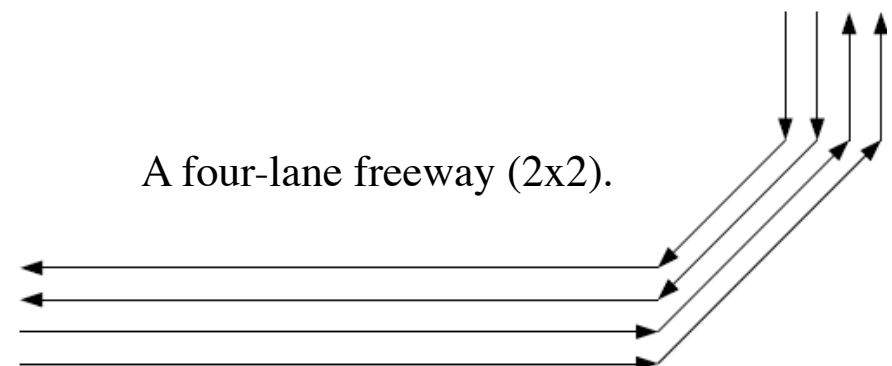
Synthetic model – Reference Point Group Mobility



Trajectory of one group (three MN) under RPGM

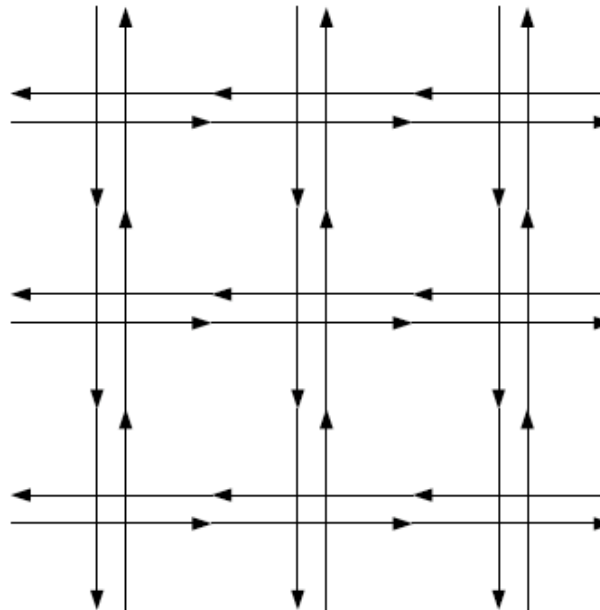
Synthetic vehicular model – Freeway [Bai03Important]

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



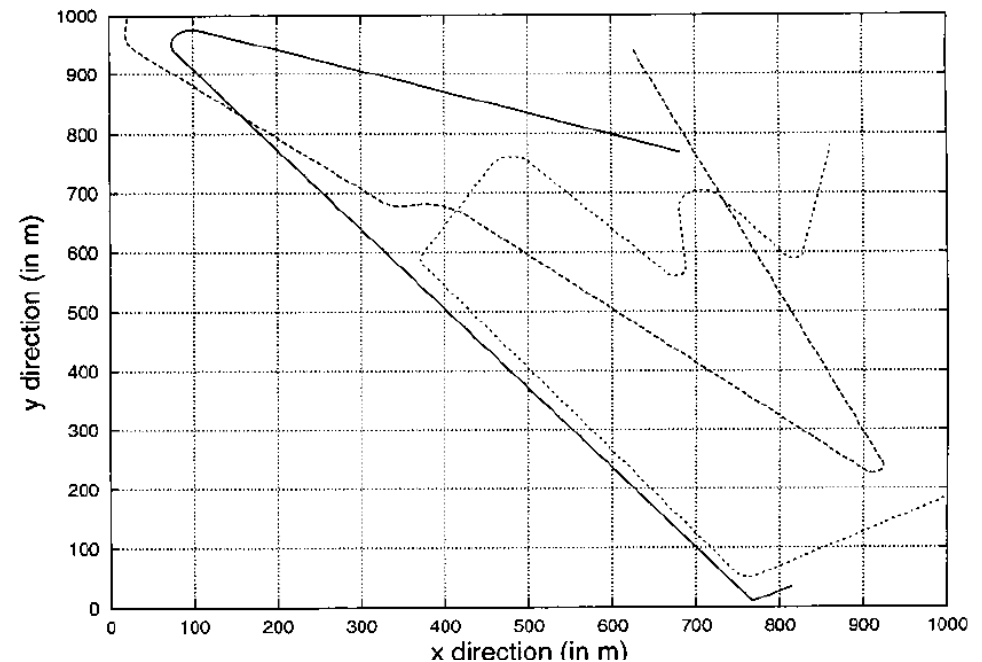
Synthetic vehicular model – Manhattan [Bai03Important]

- 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

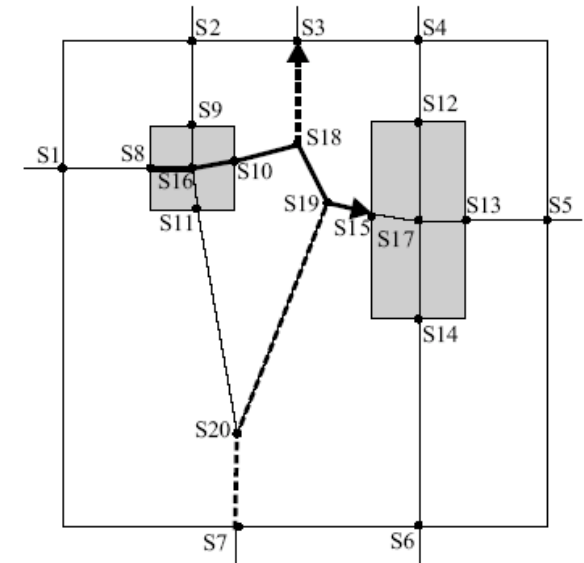


Three Smooth RWP traces

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

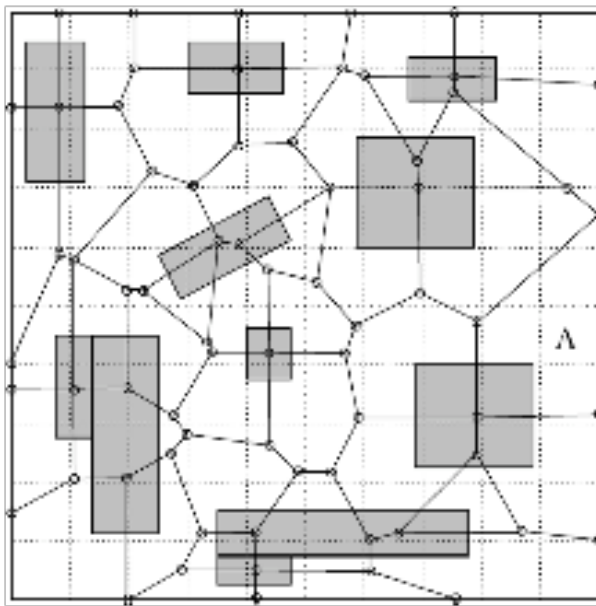
- A variation of RWP
 - The environment limits the trajectories of mobile nodes to the Voronoi graph
 - Shortest-path is computed on this graph between S-D



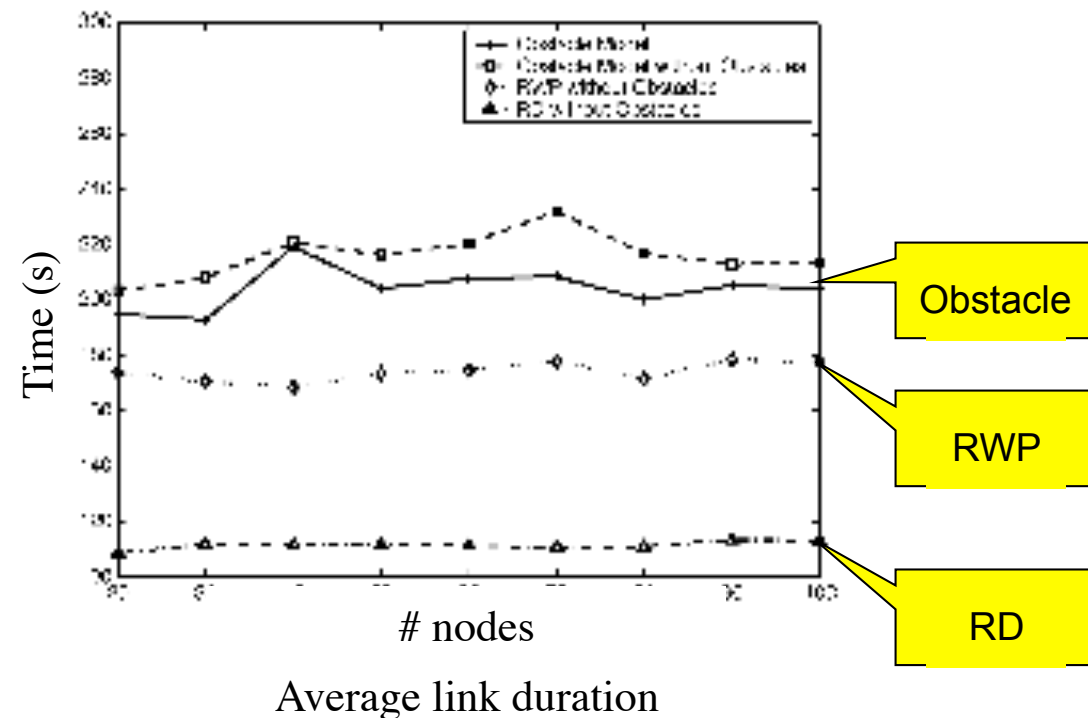
Example of trajectories
S8->S15 and S7->S3.

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



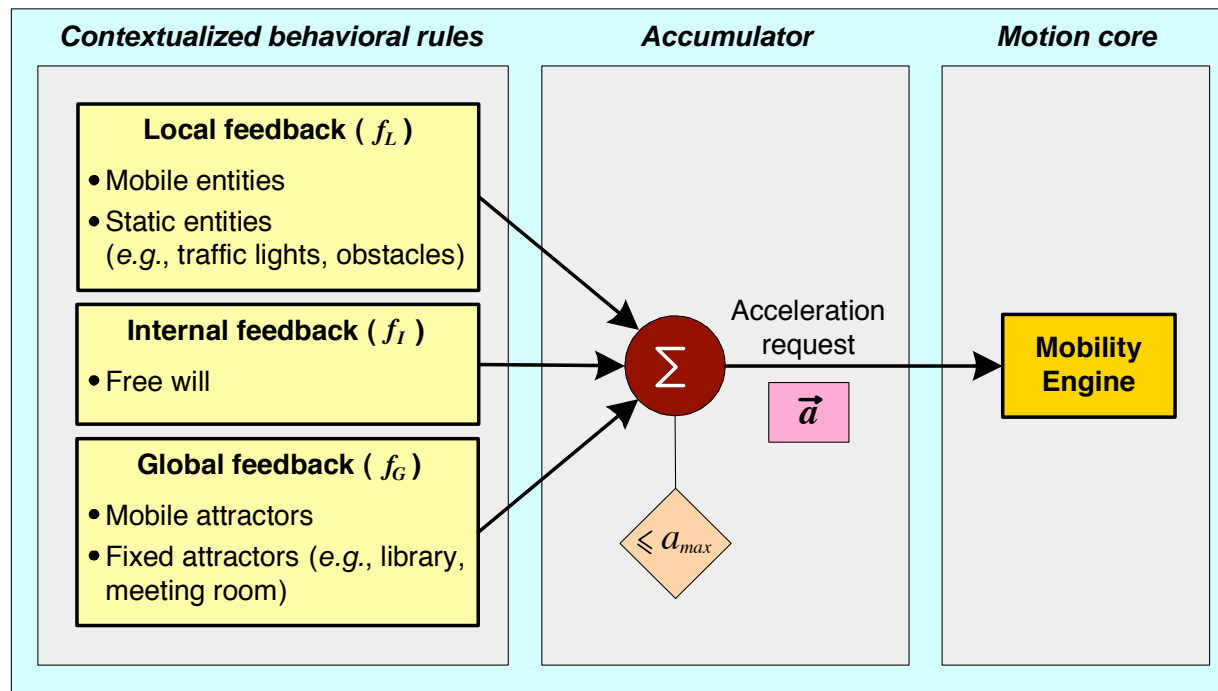
More Realistic – Behavioral Models (BM)



- 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

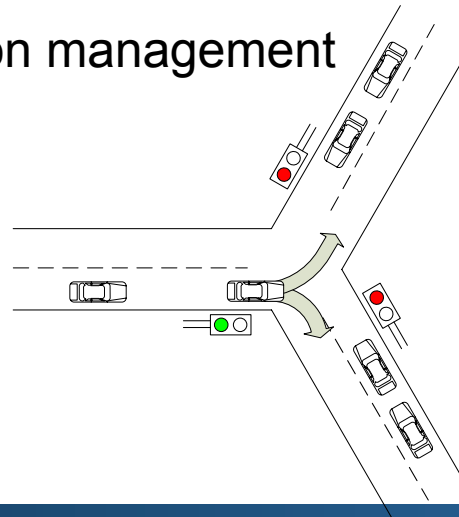
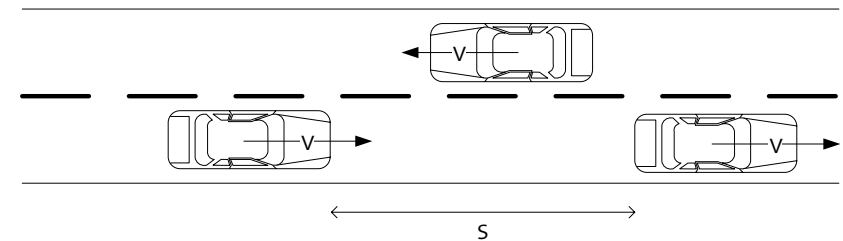
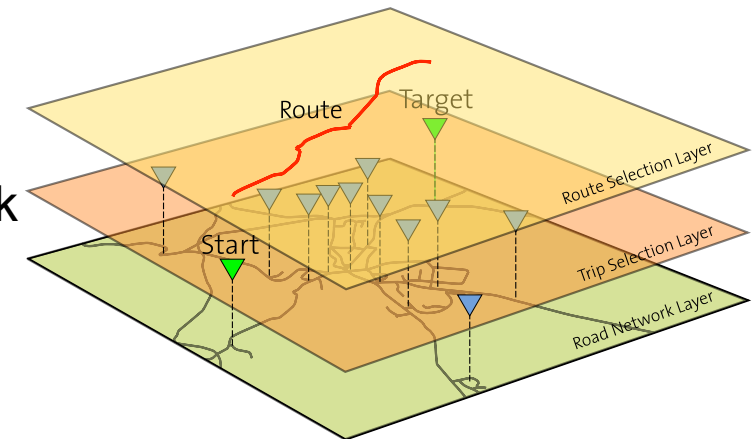
More Realistic – Behavioral Models (cont'd)

- 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

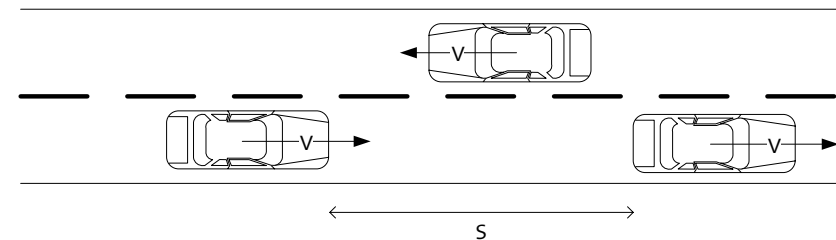


More Realistic – Vehicular behavioral Models

- 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^*

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

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

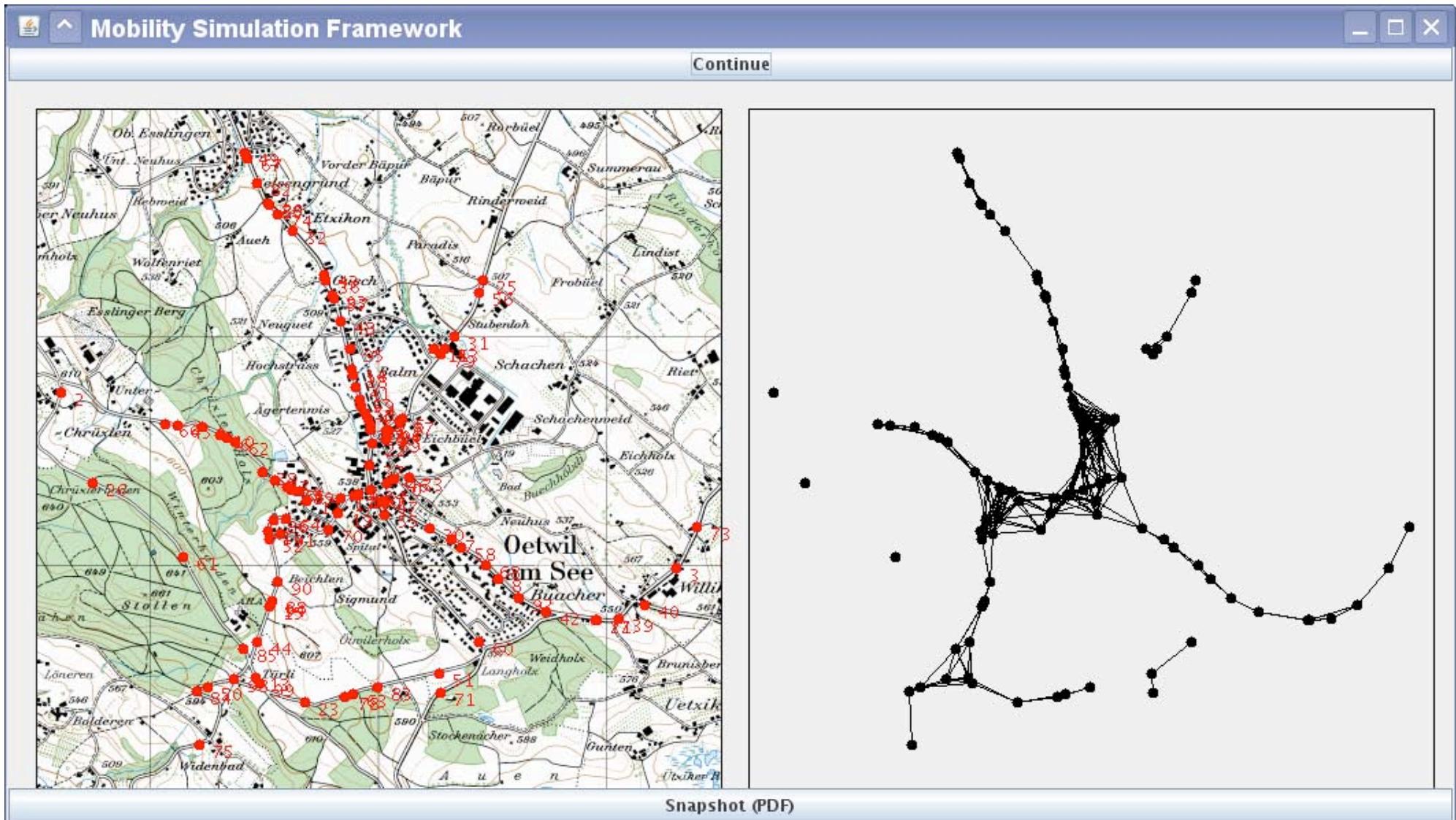


Parameter	Description	Value
v_0	Desired speed	speed limit
a	Acceleration constant	0.6
b	Deceleration constant	0.9
T	Reaction time	0.5 s
s_0	Minimal gap between vehicles	1 m

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

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

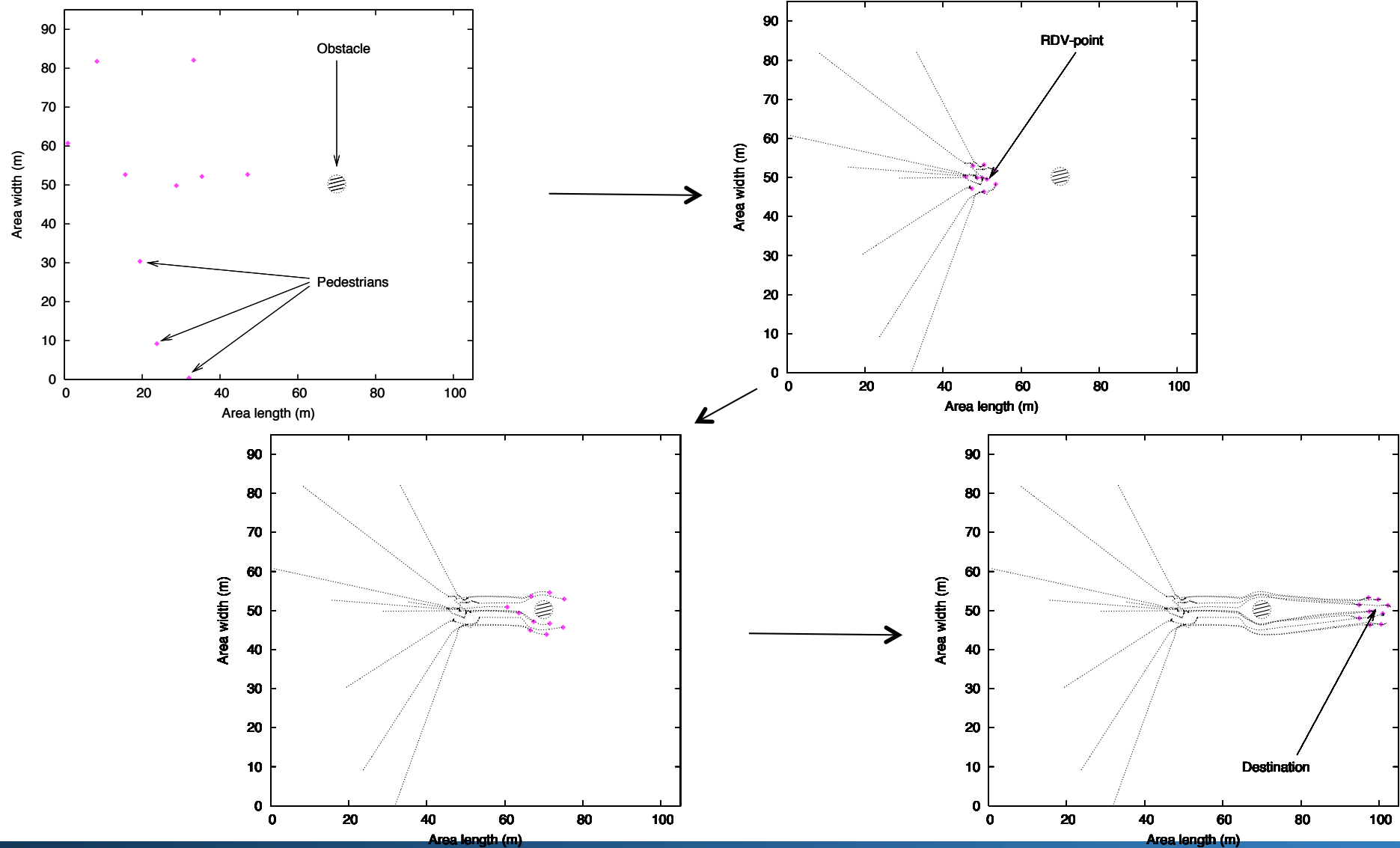
$$\vec{a}_{\text{avoidObstacle}} = \gamma(p\vec{s}_{S_i}(t) - p\vec{s}_i(t))$$

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

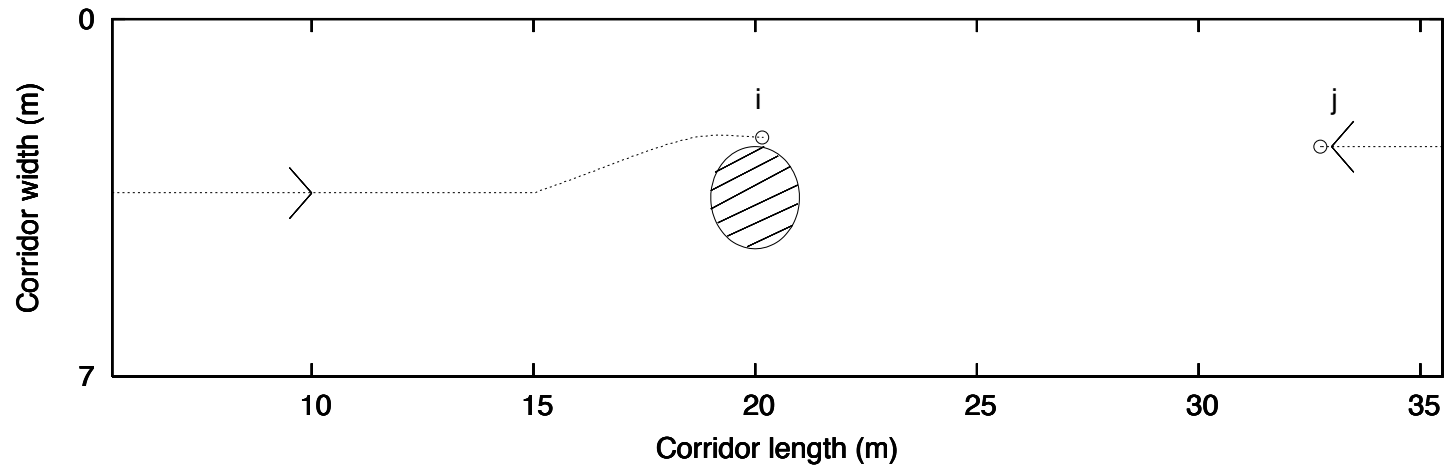
$$\vec{a}_{\text{VelocityMatching}} = \beta \left(\frac{1}{|N_G|} \sum_{z \in G} \vec{v}_z(t) \right) - \vec{v}_i(t)$$

$$\vec{a}_{\text{GroupCentering}} = \gamma \left(\frac{1}{|N_G|} \sum_{z \in G} p\vec{s}_z(t) \right) - p\vec{s}_i(t)$$

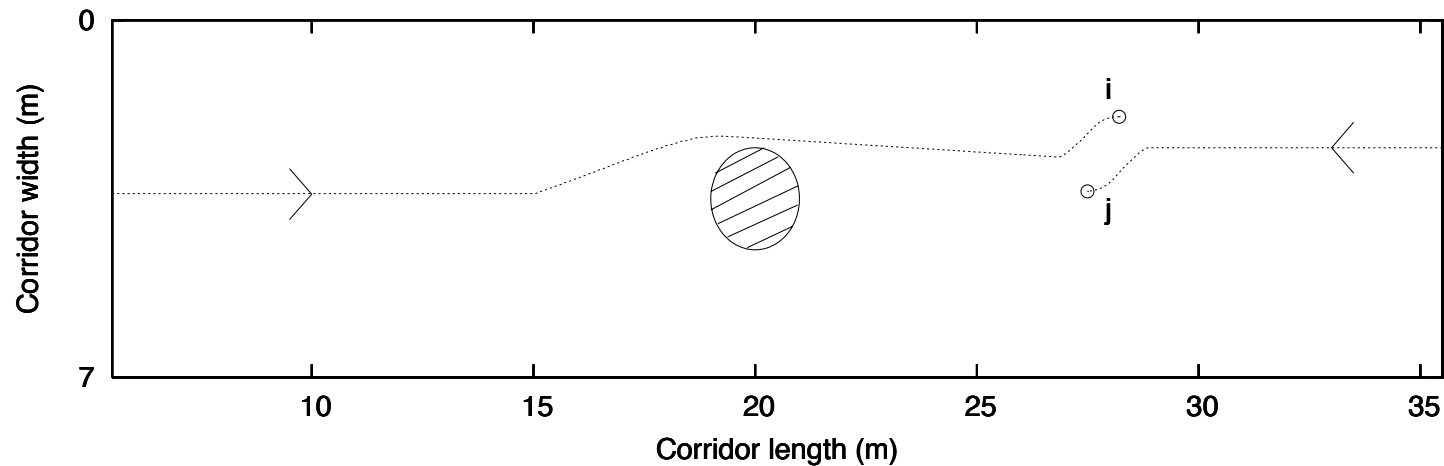
More Realistic – Behavioral pedestrian motion



More Realistic – Behavioral pedestrian motion (cont'd)



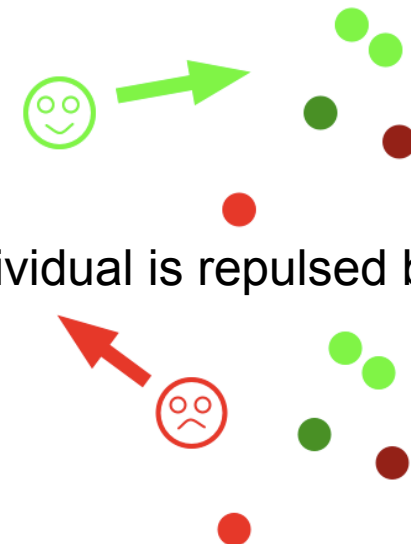
(a) At t=18 s: obstacle avoidance of pedestrian i.



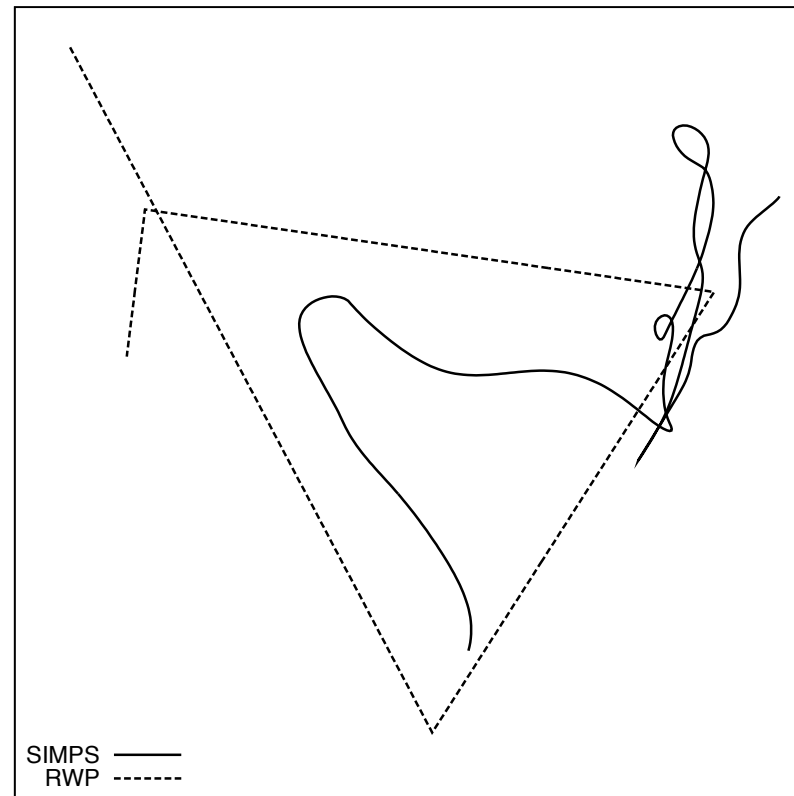
(b) At t=24.5 s: mutual avoidance of pedestrians i and j.

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



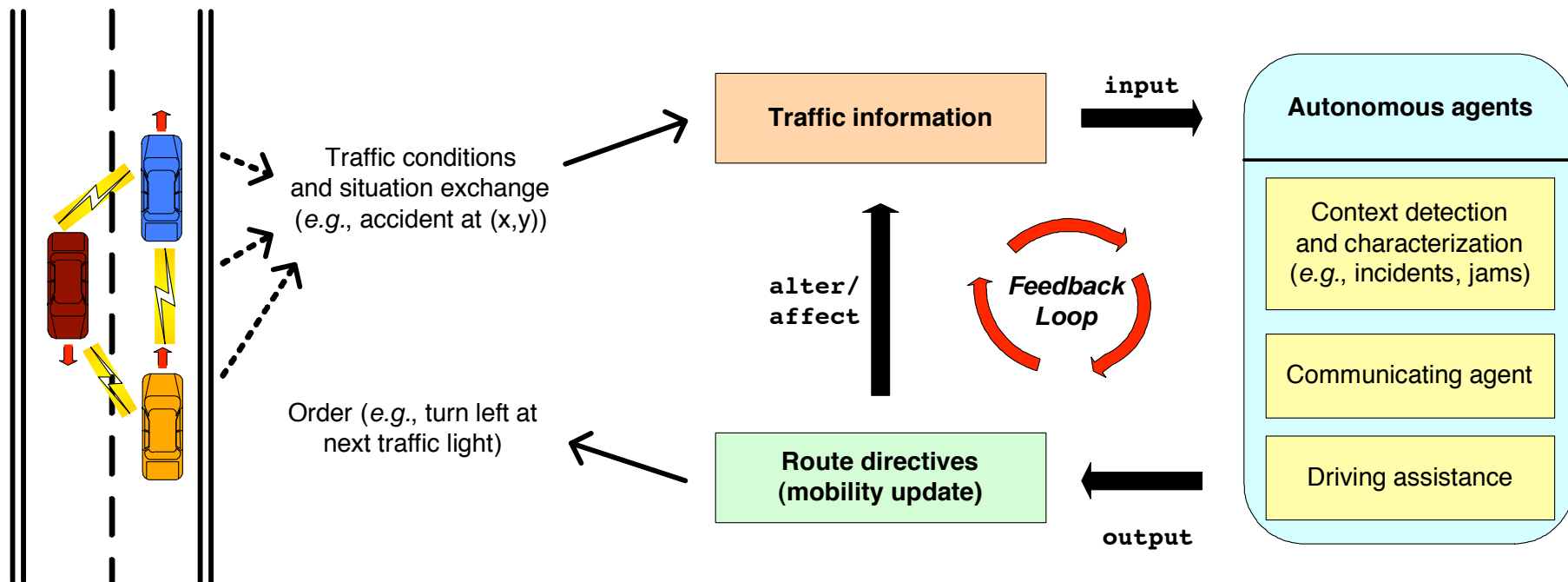
More Realistic – Social



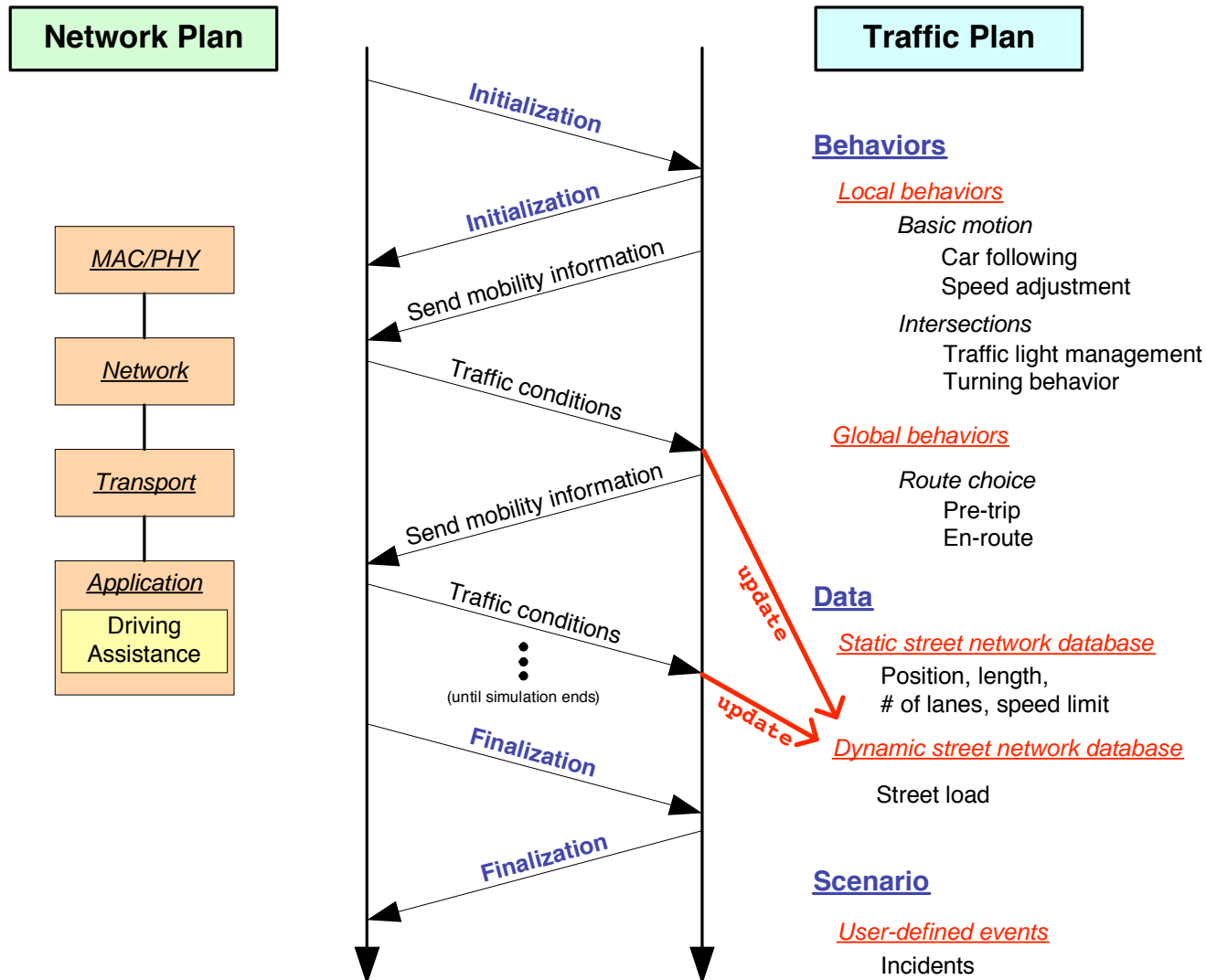
Comparative trajectories of RWP and SIMPS.

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

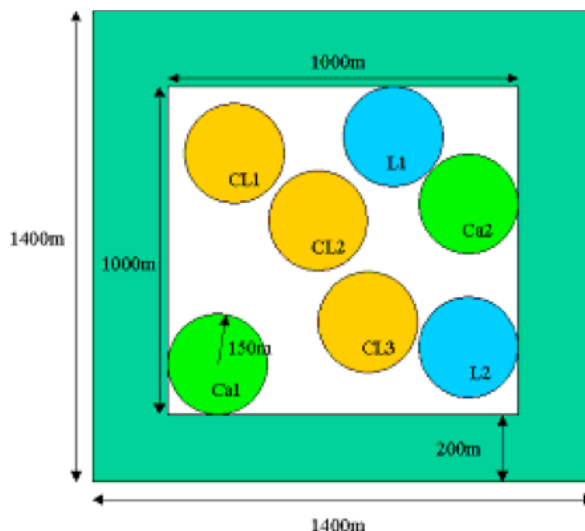
- Observe or survey people
- E.g.,
 - Brown with its microscope: Brownian motion (1827)
 - People overlooking pedestrians from top of buildings

- Trace-based models

- Traffic sensors on roads
- GPS recordings
 - Students on Campus [Dartmouth], Buses [Seattle], Taxis
- Radio contacts (RFID, Bluetooth, Wifi) [**Crowdad**]
 - MIT, UCSD, Cambridge, ETH

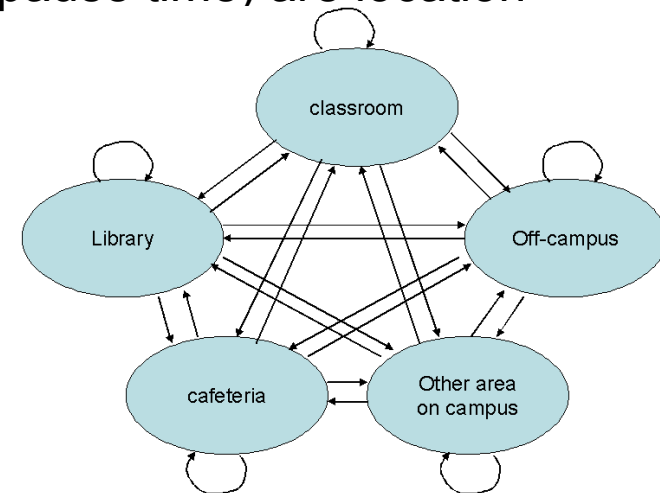
More Realistic – Surveys

- 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

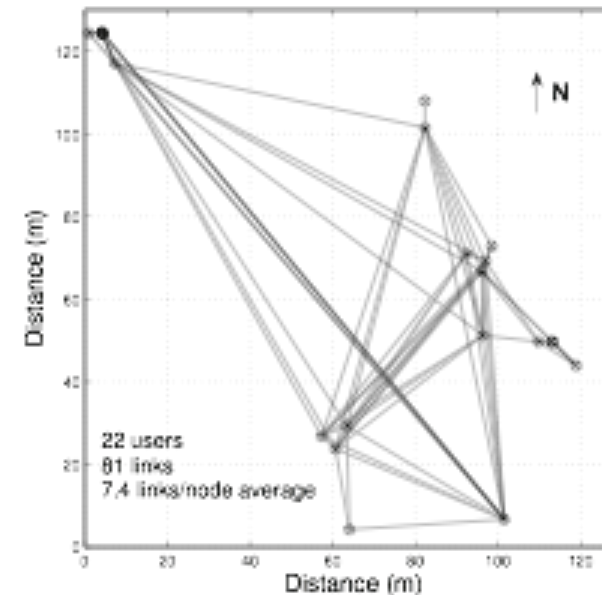
- Example of traces are Dartmouth campus [Kim06Extracting]
 - Student traced for several weeks with GPS-enabled devices



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: $O((n + o). \log(n + o))$
 - n : number of mobile entities
 - o : number of obstacles
 - Application of rules to each entity: $O(m.n)$
 - m : number of rules combined simultaneously
 - Since $(n + o) \gg m$ overall complexity is $O((n + o). \log(n + o))$
- Complexity of synthetic models
 - $O(n.m)$ (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)

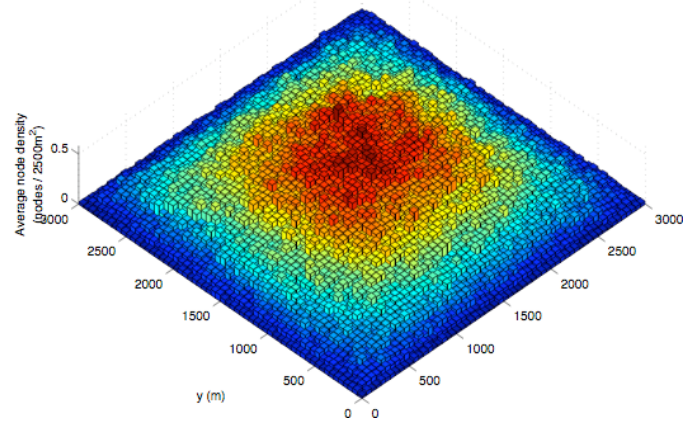
- Complexity of trace-replaying
 - $O(1)$
- Complexity of trace analysis
 - Can rapidly become *NP*-hard

Mobility Models – Metric comparison

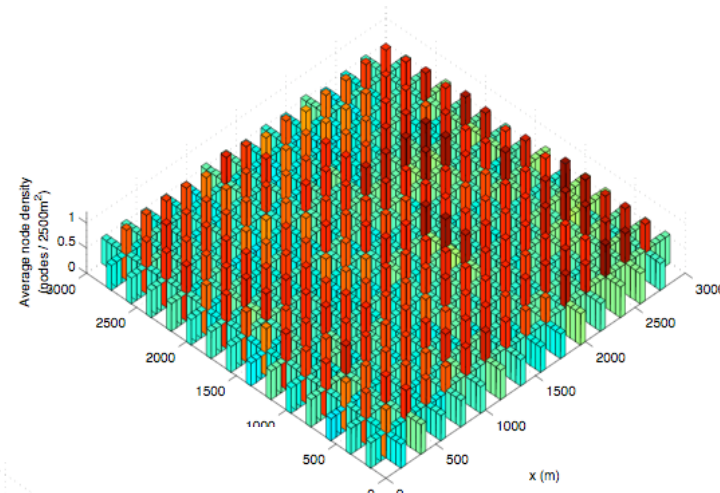
- Important Metrics [**Bai03**Important]
 - Node density
 - Relative movement direction
 - Number of Neighbors
 - Link lifetime (contact duration)
 - Network graph

Mobility Models – Metric comparison

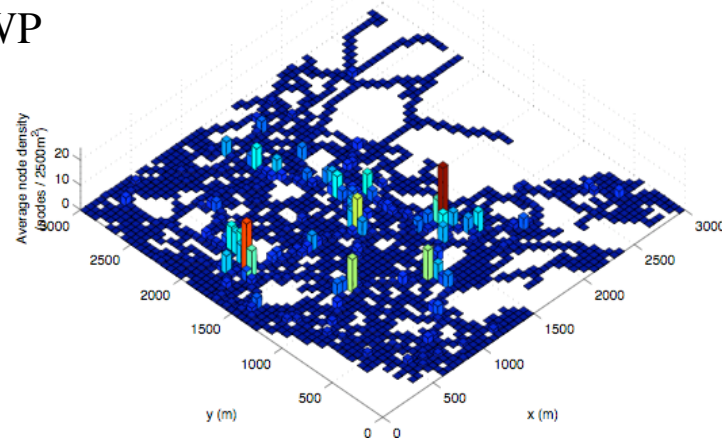
■ Node Density



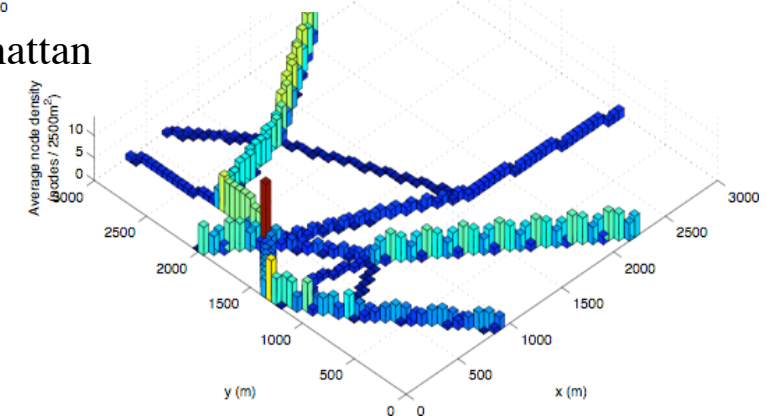
RWP



Manhattan



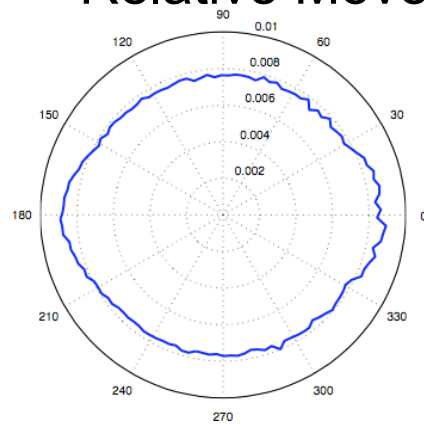
Vehicular BM



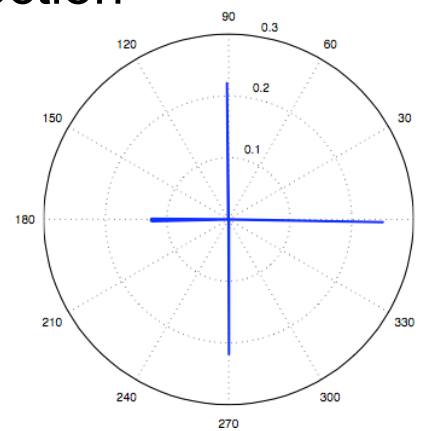
Vehicular traces
(ETH ITS group)

Mobility Models – Metric comparison

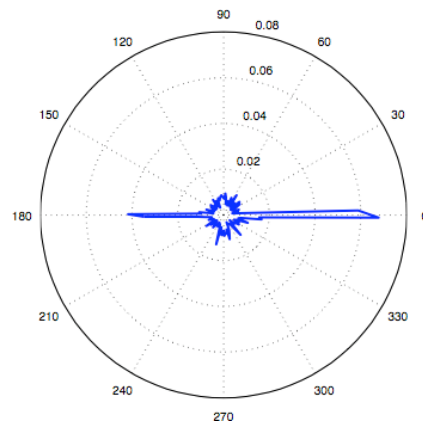
- Relative Movement Direction



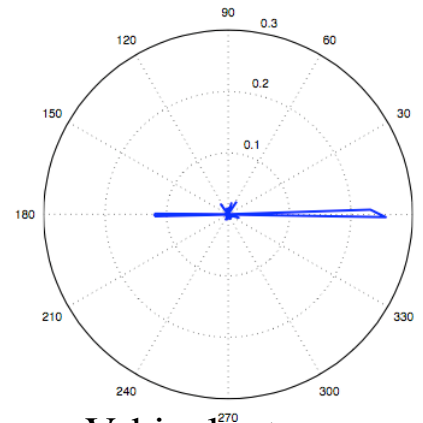
RWP



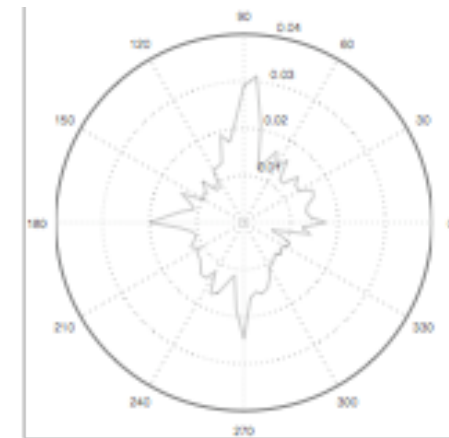
Manhattan



Vehicular BM



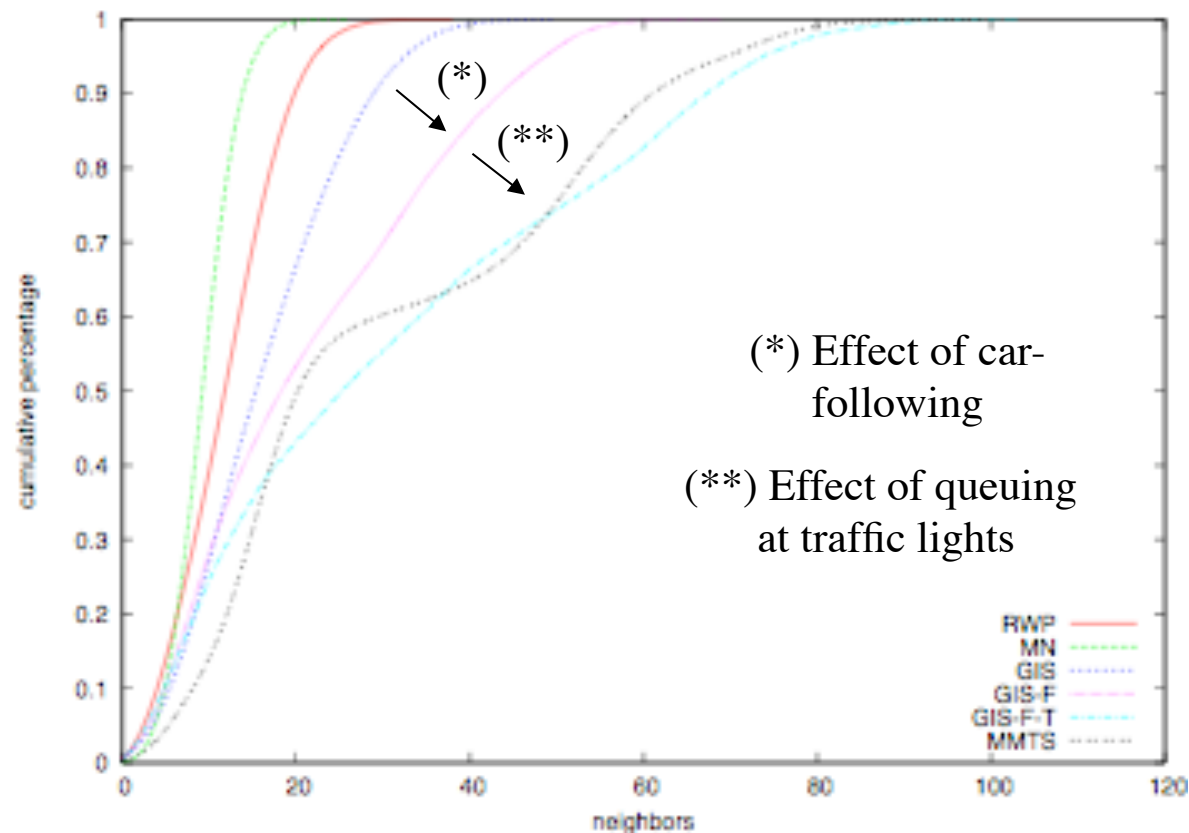
Vehicular traces
(ETH ITS group)



From GPS traces
of students on
Campus
(Dartmouth)

Mobility Models – Metric comparison

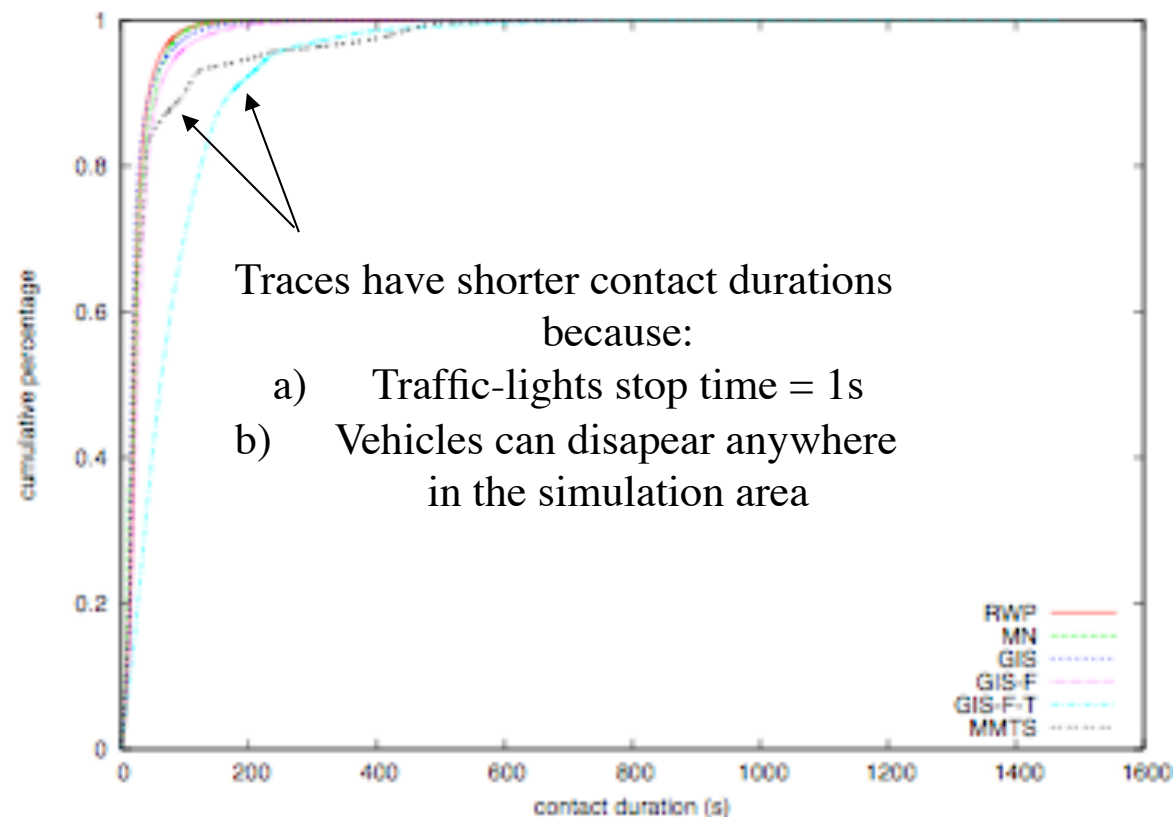
- Node degree CDF



RWP vs. MN vs. Vehicular BM vs. Traces

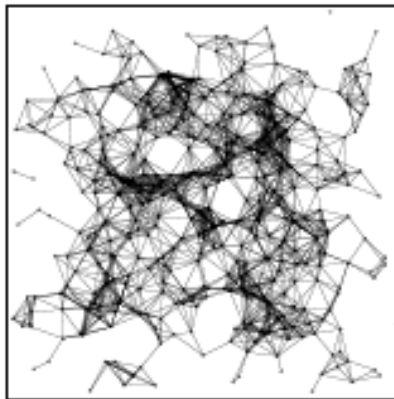
Mobility Models – Metric comparison

- Contact duration CDF (link lifetime)

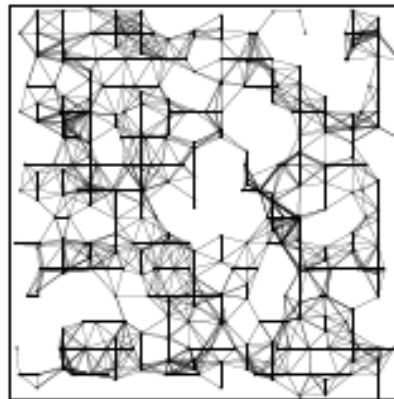


Mobility Models – Metric comparison

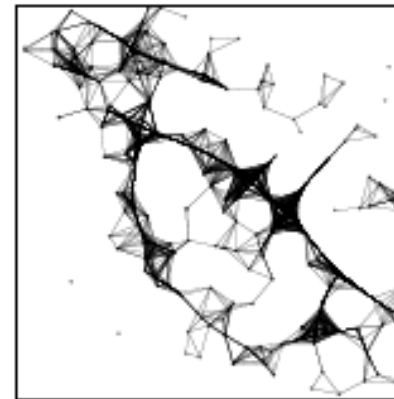
- Network Graph (snapshots)



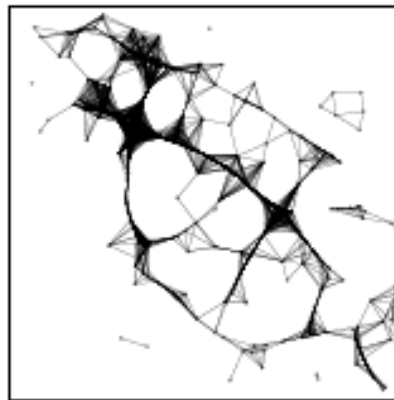
(a) Random Waypoint Model



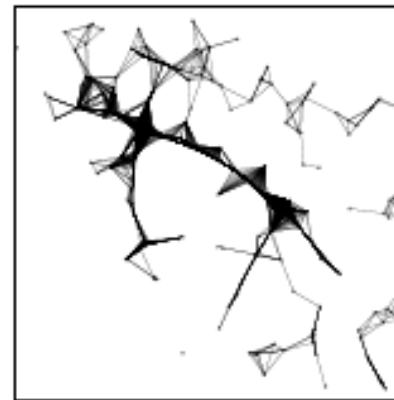
(b) Manhattan Model



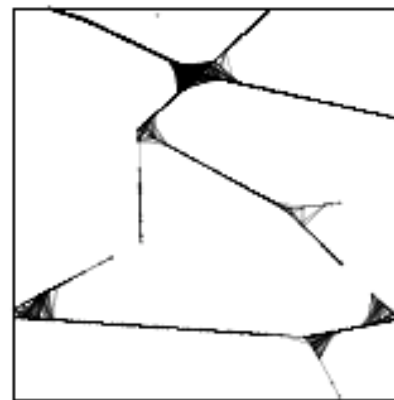
(c) GIS Model



(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

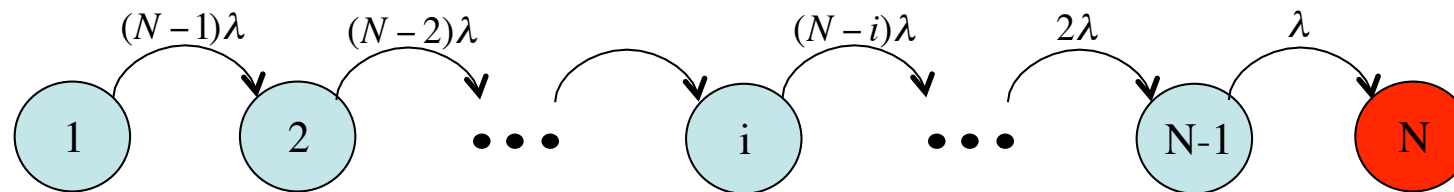
Perf. Evaluation – Example of System to evaluate

- 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 λ (rate of inter-node encounters)
 - Performance evaluation
 - What is the **delay** until all nodes get the content?

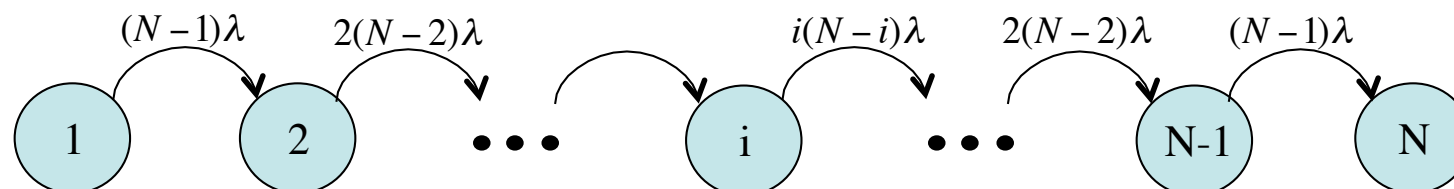
Perf. Evaluation – System formalization

- 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

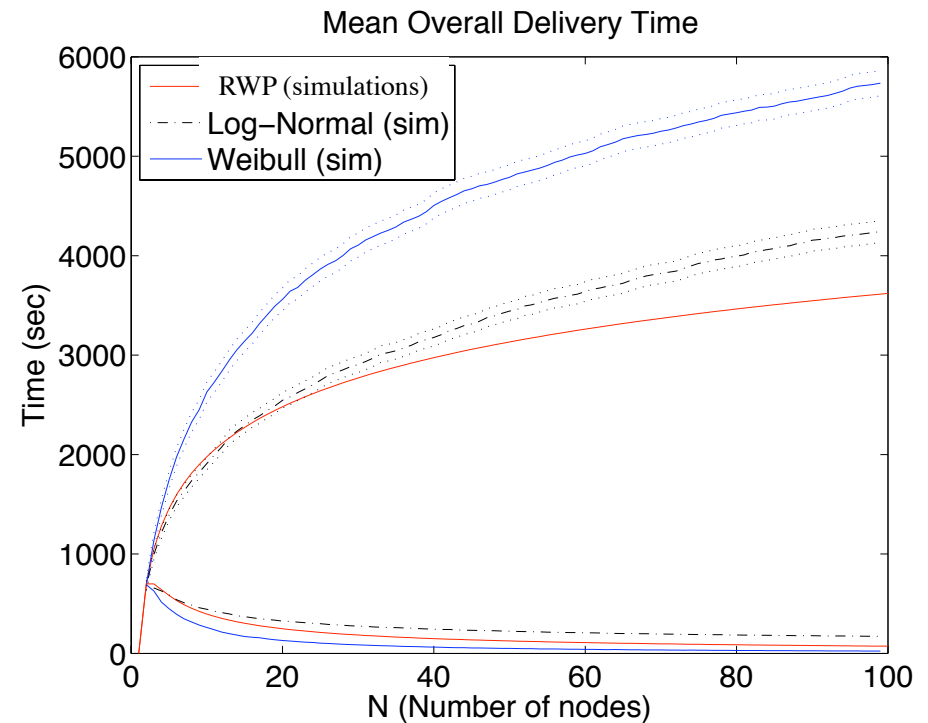
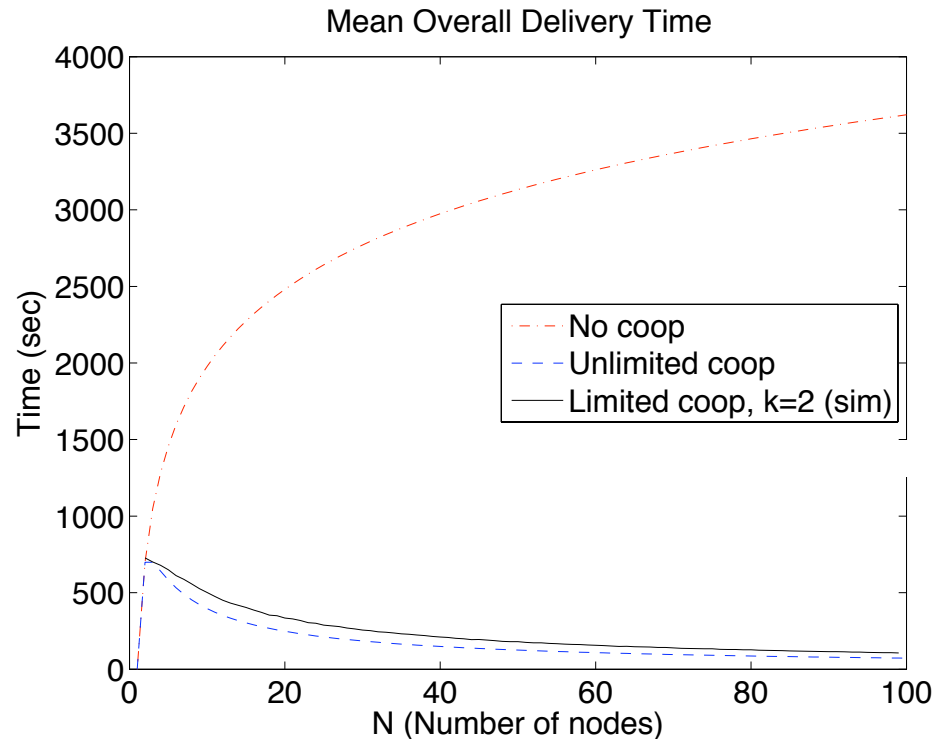
$$E[T_{odt}] = \frac{2}{\lambda N} \left(\gamma + \ln(N-1) + O\left(\frac{1}{N-1}\right) \right)$$

- Note*

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

Perf. Evaluation – System resolution

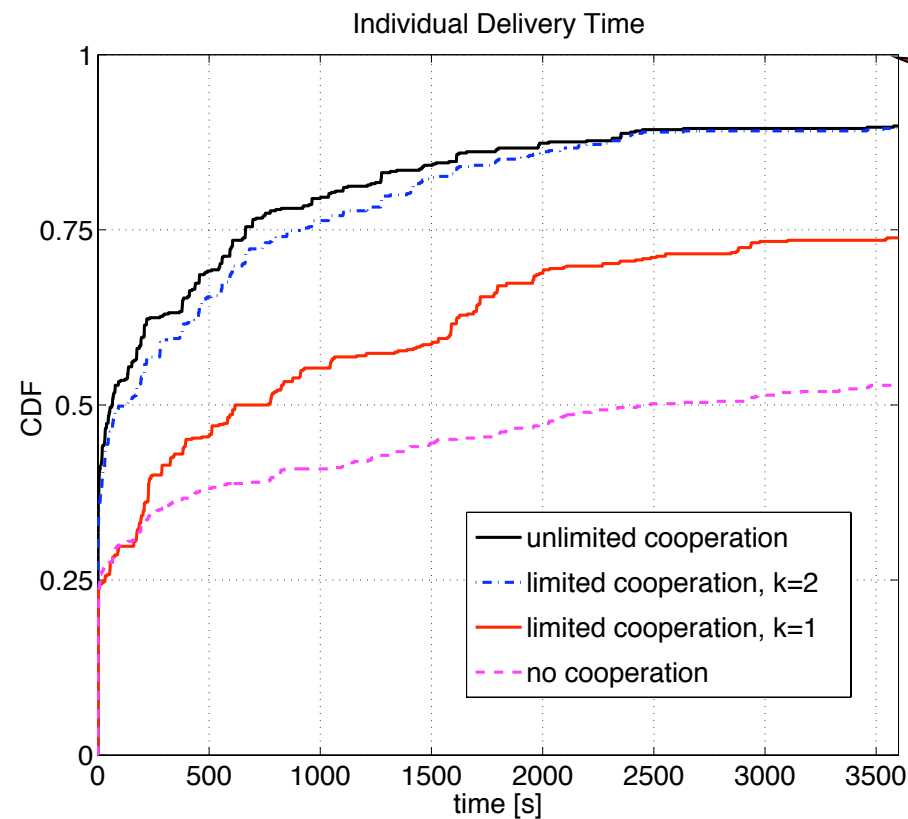
- Numerical evaluation of closed-form equations (l.) vs. simulations (r.)



- 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

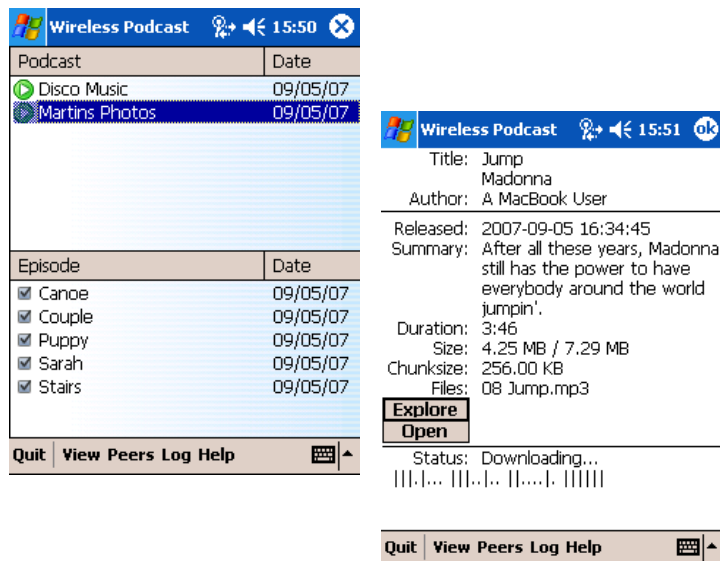
- Replaying traces also confirms the analytical results (black vs. pink)



CDF does not converge to 1 because the empirical inter-contact distribution has infinite mean (see next lectures)

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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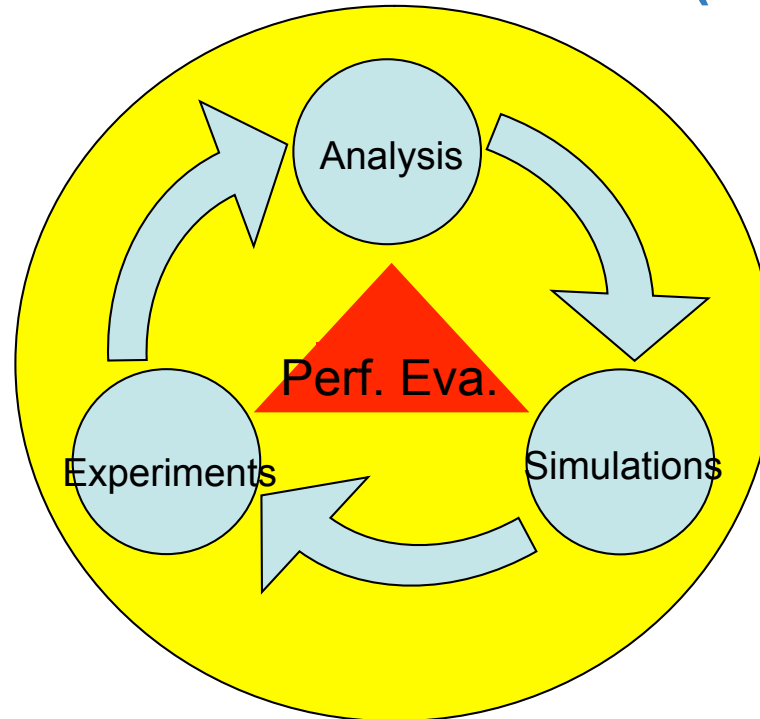
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Performance Evaluation – Conclusion (cont'd)



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

Papers you should definitely read

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Questions? Discussion ...

