A Design of Void Node Detection Techniques for Depth Based Routing in UWSN

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Abstract: -Underwater wireless sensor networks (UWSNs) have been showed as a promising technology to monitor and explore the ocean of traditional undersea wire line instruments. Nevertheless, the data gathering of UWSNs is still severely limited because of the acoustic channel communication characteristics. One way to improve the data collection in UWSNs is through the design of routing protocols considering the unique characteristics of the underwater acoustic communication and the highly dynamic network topology. In this paper, we will design routing protocol for void node detection in underwater wireless sensor network. In this paper, we propose the GEDAR routing protocol for UWSNs. GEDAR is an anycast, geographic and opportunistic routing protocol that routes data packets from sensor nodes to multiple sonobuoys at the sea's surface. When the node is in a communication void region, GEDAR switches to the recovery mode procedure which is based on topology control through the depth adjustment of the void nodes, instead of the traditional approaches using control messages to discover and maintain routing paths along void regions.

Keywords: Underwater sensor network, void node, geographic routing, routing protocol

I. INTRODUCTION

OCEANS represent more than 2/3 of the Earth's surface. These environments are extremely important for human life because their roles on the primary global production, carbon dioxide (CO2) absorption and Earth's climate regulation, for instance. In this context, underwater wireless sensor networks (UWSNs) have gained the attention of the scientific and industrial communities due their potential to monitor and explore aquatic environments. UWSNs have a wide range of possible applications such as to monitoring of marine life, pollutant content, geo-logical processes on the ocean floor, oilfields, climate, and tsunamis and seaquakes; to collect oceanographic data, ocean and offshore sampling, navigation assistance, and mine recognition, in addition to being utilized for tactic surveillance applications .Acoustic communication has been considered as the only feasible method for underwater communication in UWSNs. High frequency radio waves are strongly absorbed in water and optical waves suffer from heavy scattering and are restricted to short-range-line-of-sight applications. Nevertheless, the underwater acoustic channel introduces large and variable delay as compared with radio frequency (RF) communication, due to the speed of sound in water that is approximately $1.5*10^3$m/s[16] (five orders of magnitude lower than the speed of light ($3*10^8$m/s))[16]; temporary path loss and the high noise resulting in a high bit error rate; severely limited bandwidth due to the strong attenuation in the acoustic channel and multipath fading; shadow zones; and the high communication energy cost, which is of the order of tens of watts. In this context, geographic routing paradigm seems apromising methodology for the design of routing protocols for UWSNs . Geographic routing, also called of position-based routing, is simple and scalable. It does not require the establishment or maintenance of complete routes to the destinations. Moreover, there is no need to transmit routing messages to update routing path states. Instead, route decisions are made locally. At each hop, a locally optimal next-hop node which is the neighbour closest to the destination is selected to continue forwarding the packet. This process proceeds until the packet reaches its destination. Geographic routing can work together with opportunistic routing (OR) (geo-opportunistic routing) to improve data delivery and reduce the energy consumption relative to packet retransmissions. Using opportunistic routing paradigm, each packet is broadcast to a forwarding set composed of neighbours. In this set, the nodes are ordered according to some metric, defining their priorities. Thus, a next-hop node in the for-warding set that correctly received the packet, will forward it only whether the highest priority nodes in the set failed into do so. The next-hop forwarder node will cancel a scheduled transmission of a packet if it hears the transmission of that packet by a higher priority node. In our paradigm, the packet will be retransmitted only if none of the neighbours in the set receives it. The main disadvantage of geo-opportunistic routing is the communication void region problem. The communication void region problem occurs whenever the current forwarder node does not have a neighbor node closest to the destination than itself, i.e., the current forwarder node is the closest one to the destination. The node located in a communication void region is called void node. Whenever a packet gets stuck in a void node, the routing protocol should attempt to route the packet using some recovery method or it should be discarded.

II. RELATED WORK

Routing in UWSN is an important issue and it has been investigated by many approaches. Yan et. al. [2] proposed the DBR (Depth-based routing) protocol where the decision of forward the packet is based on the node depth and the depth of the previous sender. Upon receiving a packet, a node compares its own depth with the depth of the previous sender. If the node is closer to the water surface, it is candidate to forward the packet. DBR employs a greedy mechanism to advance the packet towards the destination in each hop. However, it does not have any recovery strategy to deal with the void region problem. Safia Gul, Sana Hoor Jakhio and Imran Ali Jokhio in [1] discussed a light weight depth based routing (LDBR) based on depth information of sensor nodes which efficiently forwards the packet to the water surface and reduces the energy consumption. The decision to forward a packet in LDBR is based on the measurement of two parameters those are the depth of the sender sensor node and the relay sensor node.A light-weight and robust depth based routing (LDBR) is developed as an extension to the actual DBR protocol. In LDBR there is an void node detection problem. Peng Xie1, Jun-Hong Cui1, and Li Lao2 proposed a vector based forwarding in [3]. Vector-Based Forwarding (VBF) protocol addresses the node mobility issue in a scalable and energy-efficient way. In VBF, each packet carries the positions of the sender, the target and the forwarder (i.e., the node which forwards this packet). The forwarding path is specified by the routing vector from the sender to the target. VBF is essentially a geographic routing protocol. To our best knowledge, VBF is the first effort to apply the geo-routing approach in underwater sensor networks

In [4] Clustering Depth Based Routing is based on existing Depth Based Routing (DBR) protocol. In DBR, routing is based on the depth of the sensor nodes: the nodes having less depth are used as forward nodes and consumes more energy as compared to the rest of nodes. As a result, nodes nearer to sink dies first because of more load. In cDBR, cluster based approach is used. In order to minimize the energy consumption, load among all the nodes are distributed equally. The energy consumption of each node is equally utilized as each node has equal probability to be selected as a Cluster Head (CH). This improves the stability period of network from DBR. In cDBR Cluster Heads (CHs) are used for forwarding packets that maximizes throughput of the network.
Daeyoup Hwang, Dongkyun Kim [9] proposed a DFR protocol. DFR relies on a packet flooding technique to increase the reliability. However, the number of nodes which flood a packet is controlled in order to prevent a packet from flooding over the whole network and the nodes to forward the packet are decided according to the link quality. In addition, DFR also addresses a well-known void problem by allowing at least one node to participate in forwarding a packet. Their simulation study using ns-2 proves that DFR is more suitable for UWSNs especially when links are prone to packet loss.

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III. PROPOSED METHODOLOGY

- GEDAR is an anycast, geographic and opportunistic protocol that tries to deliver a packet from a source node to some sonobuoys. During the course, GEDAR uses the greedy forwarding strategy to advance the packet, at each hop,towards the surface sonobuoys.
- A recovery mode procedure based on the depth adjustment of the void node is used to route data packet when it get stuck at a void node. The proposed routing protocol employs the greedy for-warding strategy by means of the position information of the current forwarder node, its neighbors, and the known sonobuoys, to determine the qualified neighbors to continue forwarding the packet towards some sonobuoys.
- Despite greedy forwarding strategy being a well known and used next-hop forwarder selection strategy, GEDAR considers the anycast nature of underwater routing when multiple surface sonobuoys are used as sink nodes.
- GEDAR overcomes the problem of the void region by depth adjustment technology.
- The impacts of nodes movement on the void area have not been investigated thoroughly. The void area is continuously reshaped or move with the water current[12]. We will work for investigating the impact of node movement.
- With a cross-layer design, the number of collisions can be managed more efficiently over the MAC layer, while the results of some tasks, such as beaconing, can be shared between layers.
- Dealing with a void area within a geocast region is an challenging issue. The existing model involves many relay nodes to cover the geocast region with a larger area. Hence, we design the new void-handling techniques to further decrease the number of involving node.

System Architecture

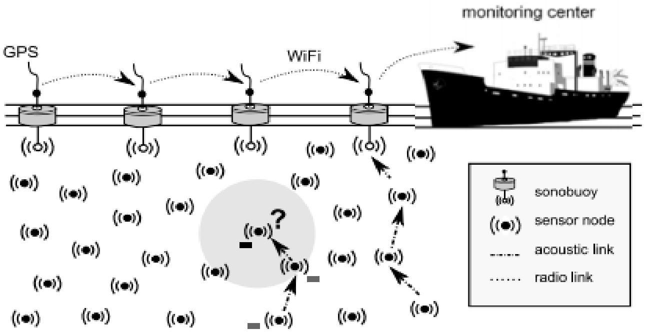

Fig. 3: Architecture of UWSN with a void region problem

As shown in Fig. 2 we have a large number of mobile underwater sensor nodes at the ocean bottom and sonobuoys, also named sinks nodes, at the ocean surface. They move as a group with the water current [16]. It will transfer the data from sonobuoy to monitoring center.

Data Flow Diagram

Advantages of proposed system:

- The works proposed a node’s depth adjustment to improve data packet delivery in static underwater sensor networks.
- Differently, our node’s depth adjustment algorithm is devoted to the communication void region routing problem in mobile underwater sensor networks, acting in a reactive way to overcome changes in the network topology.
- Moreover, we implement an opportunistic routing mechanism to mitigate the impairments of the underwater acoustic communication.

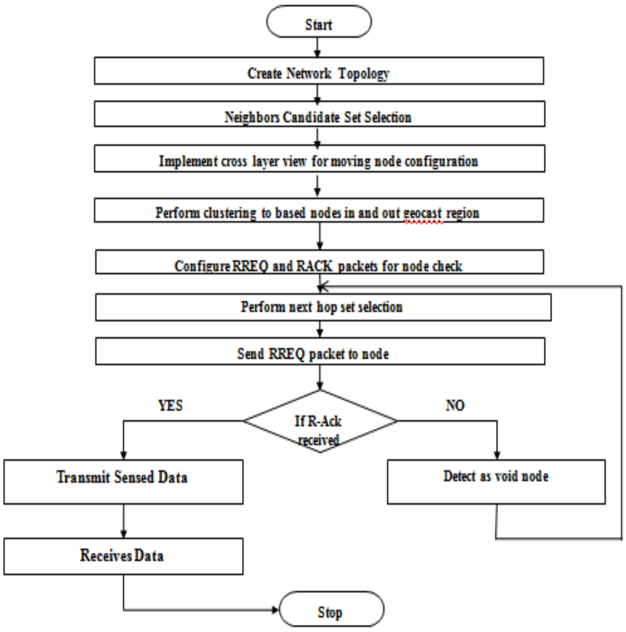

Fig. 2: Data flow diagram

Topology Creation

In our simulations, the 32 number of sensor nodes are deployed and the number of sonobuoys is 6. They are randomly deployed in a region the size of 2265 X 1000. In each sensor, data packets are generated according to a Poisson process with the same parameter to very low traffic load; to simulate a mobile network scenario, considers the effect of meandering sub-surface currents (or jet streams) and vertices. We set the main jet speed range from max 5 m/s to min 2.70 m/s. the nodes have a transmission range (rc) of 250 m and a data rate of 50 kbps. The size of the packet is deter-mined by the size of the data payload and by the space required to include the information of the next-hop for-warder set. We consider that data packets have a payload of 150 bytes

Enhanced Beaconing

Periodic beaconing plays an important role in GEDAR. It is through periodic beaconing that each node obtains the location information of its neighbors and reachable sonobuoys, where each node can be informed beforehand concerning the location of all sonobuoys (as long-term underwater monitoring architecture is formed by static nodes attached to buoys and/or anchors), we need an efficient beaconing algorithm that keeps the size of the periodic beacon messages short as possible. We propose an enhanced beacon algorithm that takes this problem into consideration. Similarly, each sensor node embeds a sequence number, its unique ID and X, Y, and Z position information. Moreover, the beacon message of each sensor node is augmented with the information of its known sonobuoys from its set $S_i(t)$.Each node includes the sequence number, ID, and the X, Y location of the its known sonobuoys. The goal is for the neighboring nodes to have the location information of the all reachable sonobuoys. GPS cannot be used by underwater sensor nodes to determine their locations given that the high frequency signal is rapidly absorbed and cannot reach nodes even localized at several meters below the surface. Thus, each sensor node knows its location through localization services. Localization services incur additional costs in the network. However, the knowledge regarding the location of sensor nodes can eliminate the large number of broadcast or multicast queries that leads to unnecessary network flooding that reduces the network throughput. In addition, the location information is required to tag the collected data, track underwater nodes and targets, and to coordinate the motion of a group of nodes.In order to avoid long sizes of beacon messages, a sensor node includes only the position information of the sonobuoys it has not disseminated in the predecessor round. Whenever a node receives a new beacon message, if it has come from a sonobuoy, the node updates the corresponding entry in the known sonobuoy set. Otherwise, it updates its known sonobuoys |Si| set in the corresponding entries if the information location contained in the beacon message is more recent than the location information in its set Si. For each updated entry, the node changes the appropriate flag L to zero, indicating that this information was not propagated to its neighbors. Thus, in the next beacon message, only the entries in $S_i(t)$ in which the L is equal to zero are embedded. We add random jitters between 0 and 1 during the broadcast of beacon messages, to minimize the chance of both collisions and synchronization.

Neighbors Candidate Set Selection

Whenever a sensor node has a packet to send, it should determine which neighbors are qualified to be the next-hop forwarder. GEDAR uses the greedy forwarding strategy to determine the set of neighbors able to continue the forwarding towards respective sonobuoys. The basic idea of the greedy forwarding strategy is, in each hop, to advance the packet towards some surface sonobuoy. The neighbor candidate set is determined as follows. Let ni be a node that has a packet to deliver, let its set of neighbors be and the set of known sonobuoys $S_i(t)$at time t. We use the packet advancement (ADV) metric to deter-mine the neighbors able to forward the packet towards some destination. The packet advancement is defined as the distance between the source node S and the destination node D minus the distance between the neighbor X and D.Thus, the neighbors candidate set in GEDAR is given as:

$$C_i = \{n_k \in N_i(t) : \exists s_v \in S_i(t) \mid D(n_i, s_i^*) - D(n_k, s_v) >$$

[16]

Where D(a,b) is the euclidean distance between the nodes a and b and $s_i^* \in S_i(t)$,is closest sonobuoy of ni as:

$$s_i^* = argmin_{\forall s_j \in S_i(t)} \{D(n_i, s_j)\}. \quad [16]$$

Next-Hop Forwarder Set Selection

GEDAR uses opportunistic routing to deal with under-water acoustic channel characteristics. In traditional multihop routing paradigm, only one neighbor is selected to act as a next-hop forwarder. If the link to this neighbor is not performing well, a packet may be lost even though other neighbor may have overheard it. In opportunistic routing, taking advantage of the shared transmission medium, each packet is broadcast to a forwarding set composed of several neighbors. The packet will be retransmitted only if none of the neighbors in the rest receive it. Opportunistic routing has advantages and disadvantages that impact on the network performance. OR reduces the number of possible retransmissions, the energy cost involved in those retransmissions, and help to decrease the amount of possible collisions. However, as the neighboring nodes should wait for the time needed to the packet reaches the furthest node in the forwarding set, OR leads to a high end-to-end latency. For each transmission, a next-hop forwarder set F is determined. The next-hop forwarder set is composed of the most suitable nodes from the next-hop candidate set Ci so that all selected nodes must hear the transmission of each other aiming to avoid the hidden terminal problem. The problem of finding a subset of nodes, in which each one can hear the transmission of all nodes, is a variant of the maximum clique problem,that is computationally hard. We use normalized advance (NADV) to measure the “goodness”of each next-hop candidate node in Ci.NADV corresponds the optimal trade-off between the proximity and link cost to determine the priorities of the candidate nodes. This is necessary because the greater the packet advancement is, the greater the neighbor priority becomes. However, due to the underwater channel fading, the further the distance is from the neighbor, the higher the signal attenuation becomes as well as the likelihood of packet loss.

Recovery Mode

Void node recovery procedure is used when the node fails to forward data packets using the greedy forwarding strategy. Instead of message-based void node recovery procedures, GEDAR takes advantage of the already available node depth adjustment technology to move void nodes for new depths trying to resume the greedy forwarding. We advocate that depth-adjustment based topology control for void node recovery is more effective in terms of data delivery and energy consumption than message-based void node recovery procedures in UWSNs given the harsh environment and the expensive energy consumption of data communication.The GEDAR depth-adjustment based topology control for a void node recovery procedure can be briefly described as follows. During the transmissions, each node locally determines if it is in a communication void region by examining its neighborhood. If the node is in a communication void region, that is, if it does not have any neighbor leading to a positive progress towards some surface sonobuoy (C¼;), it announces its condition to the neighborhood and waits the location information of two hop nodes in order to decide which new depth it should move into and the greedy forwarding strategy can then be resumed. After, the void node determines a new depth based on two-hop connectivity such that it can resume the greedy forwarding.

IV. CONCLUSION

Void node detection has been one of the most important issues in underwater applications. In this paper, we introduced a novel geographic and opportunistic routing protocol (GEDAR), for underwater mobile sensor networks. GEDAR uses the position information of the nodes to greedily forward data packets to sonobuoy. Instead of message-based procedures to deal with the communication void region problem found in geographic routing for mobile underwater sensor networks, we proposed a depth adjustment-based topology control such that void nodes move to new depths to resume the greedy opportunistic forwarding.

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