

Carrier Offset and Channel Estimation for Cooperative MIMO Sensor Networks

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Abstract—A cooperative MIMO network is considered with N_s sensors and a collector node with M_c antennas. In a practical implementation of this network, the sensor carriers have relative frequency offsets which must be estimated along with the MIMO channel. Generalized successive interference cancellation (GSIC) is proposed for this joint estimation problem. The primary operations in GSIC are correlation, FFT and cancellation. A reconfigurable hardware (FPGA) implementation of these GSIC primitives is described. A hybrid analysis/simulation for bit error rate (BER) is presented with results for GSIC using Alamouti and $\mathcal{G}_c^4$ codes.

I. INTRODUCTION

In a variety of scenarios, it is difficult or impossible for individual nodes in a wireless sensor network (WSN), as depicted in Fig. 1, to achieve link connectivity to a stand-off collector due to limited transmit power. While temporal coding or higher transmit power can be used to increase connectivity, these solutions are counter to the spirit of low-cost embedded wireless nodes. In addition, a WSN may only infrequently need to reach a receiver that is not co-located; it is not cost-effective to equip nodes with capabilities that will be rarely used. In this paper we provide an operational overview of our cooperative MIMO concept, discuss the GSIC algorithm for the difficult problem of joint channel/carrier offset/delay estimation, and address baseband implementation in reconfigurable hardware.

We consider the network in Fig. 1 with N_s single-antenna sensors and an uplink to an M_c element collector node. It is assumed that the N_s sensors have a common pool of data $\mathbf{b}$ to transmit, representing for example the estimated position/velocity of a jointly tracked target (labeled *Event* in the figure). Cooperative MIMO has been proposed as a method for achieving longer range and/or lower power by forming a virtual array with the sensors [1][2][3]. However, unlike point-to-point MIMO, the sensors cannot phase-lock their upconverters or symbol clocks, and thus these parameters must be jointly estimated with the MIMO channel. The GSIC algorithm [4] is a pragmatic solution to this difficult separable signal problem, and is based on successive correlation and

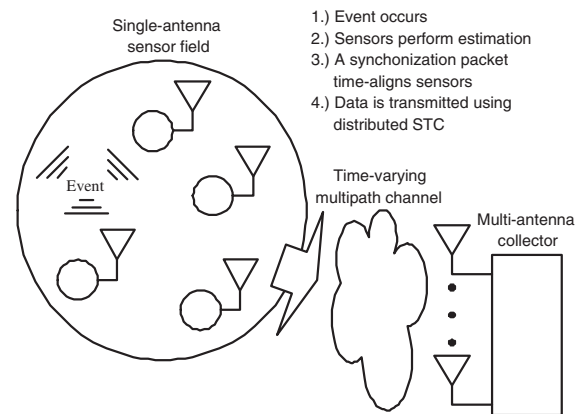


Fig. 1. Overview of operational concept.

cancellations to eliminate the exponential increase in estimator complexity using the optimal maximum-likelihood (ML) method. Specifically, each stage of GSIC corresponds to the single sensor ML solution for channel/offset/delay estimation based on cancellation of previously estimated sensor received waveforms.

In order to rapidly evaluate GSIC performance, a hybrid analysis/simulation method for BER evaluation is presented based on linear decoding [5]. It is shown that the BER for linear decoding can be computed analytically, conditioned on a given trajectory of channel realizations and estimates.

In the hardware development section of the paper we discuss RF and baseband design issues. Our primary focus for RF design is to achieve stability of the voltage-controlled oscillators (VCOs). A secondary consideration is high sensitivity to a large sum of individually low-power sensor signals. We show resource use for two candidate field programmable gate arrays (FPGA), namely Xilinx Spartan-3 and Virtex-4 devices. While many design features, such as channel tracking and decoding, are identical to those in conventional MIMO designs with co-located antenna elements, there are special considerations that must be made for parameter estimation in the cooperative

sensor problem. Since the individual sensor oscillators are not co-located, they cannot be phase-locked, and hence the received sensor offsets must be estimated individually at the collector. This design issue represents the core reason for the necessity of GSIC.

In the sequel, the cooperative MIMO channel is defined in Section II along with the GSIC algorithm for offset/channel estimation. The BER analysis/simulation method is derived in Section IV and the reconfigurable hardware design is summarized in Section V. The results of the BER analysis/simulation are given in Section VI along with conclusions.

II. COOPERATIVE MIMO CHANNEL AND ESTIMATION PROBLEM

A flat-fading channel is assumed between the N_s sensors and collector with M_c elements. The received collector signal $\mathbf{r}_c(t) \in \mathbb{C}^{M_c}$ on the uplink is then given in continuous-time by

$$\mathbf{r}_c(t) = \sum_{k=1}^{N_s} \mathbf{h}_k \sum_{m=0}^{\infty} p(t - \tau_k - mT) e^{i\delta\omega_k t} s_k(m) + \mathbf{n}(t), \quad (1)$$

where $\mathbf{h}_k \in \mathbb{C}^{M_c}$ is the flat-fading channel from sensor k to the collector, ω_k is the frequency offset in Hz for sensor k , and τ_k is the corresponding delay. The symbols $s_k(m) \in \mathbb{C}$ represent a training sequence in the estimation phase, or the m -th row and k -th column of an OSTBC matrix [5]. The symbols are normalized to $E\{|s_k(m)|^2\} = 1$. The pulses $p(t)$ are raised-cosine with minimal excess bandwidth to maximize orthogonality. The bandpass pulse energy *per sensor* is defined by $E_s = N_u \int p(t)^2 dt/2$. The parameter N_u is the number of times an information symbol is transmitted in a space-time code block, e.g. $N_u = 1$ for Alamouti and 2 for $\mathcal{G}_c^4$. The total transmitted bandpass energy is then $E_s N_s$ per information symbol for OSTBCs. Note that this is in contrast to the conventional MIMO normalization but represents the more realistic case of fixed sensor transmit power.

A discrete-time signal model is obtained by defining the matrix of samples collected from the M_c elements, $\mathbf{R}(m) \in \mathbb{C}^{N_c \times M_c}$ as

$$\mathbf{R}(m) = \sum_{k=1}^{N_s} \sum_{q=0}^{N_c-1} \mathbf{p}_{q,m}(\tau_k, \delta\omega_k) \mathbf{h}_k^T s_k(q + mN_c) + \mathbf{N}(m). \quad (2)$$

In (2), N_c corresponds to the number of symbols/training packet, or temporal length of the OSTBC, with m denoting the packet or OSTBC codeword index. The elements of $\mathbf{N}(m)$ are i.i.d. circular Gaussian with variance $2N_0/T_s$, assuming an input Nyquist bandwidth $1/(2T_s)$. The pulse vectors $\mathbf{p}_{q,m} \in \mathbb{C}^{N_c N_d}$ are defined by

$$\begin{aligned} \mathbf{p}_{q,m}(\tau_k, \delta\omega_k) = & \quad (3) \\ & \left[p((N_c N_d - 1)T_s - \tau_k - qT) e^{i\delta\omega_k(mN_c T + (N_c N_d - 1)T_s)}, \right. \\ & \left. \dots, p(-\tau_k - qT) e^{i\delta\omega_k m N_c T} \right]^T, \end{aligned}$$

where $1/T$ is the symbol rate and $N_d = T/T_s$ is the oversampling factor. Note our reconfigurable hardware solution uses $N_d = 32$ for sufficiently precise delay τ_k estimation.

Let $m = 0$ w.l.o.g. in (3). The joint estimation problem then becomes

$$\begin{aligned} \{\hat{\tau}_k, \hat{\mathbf{h}}_k, \hat{\delta\omega}_k\} = \arg \min_{\{\tau_k, \mathbf{h}_k, \delta\omega_k\}} & \quad (4) \\ \|\mathbf{R} - \sum_{k=1}^{N_s} \sum_{q=0}^{N_c-1} \mathbf{p}_q(\tau_k, \delta\omega_k) \mathbf{h}_k^T s_k(q)\|_F^2. \end{aligned}$$

where $\|\mathbf{X}\|_F$ is the Frobenius norm. The focus here is on known training symbols $s_k(q)$. Although blind MIMO channel/offset estimators have been developed [6], the required eigendecompositions are too complex for the reconfigurable hardware available here. Thus we assume Gold-sequence training packets $\{s_k(q)\}$ for estimation in eq. (4).

III. CORRELATION AND GSIC ESTIMATION ALGORITHMS

When the node symbol clocks are synchronized such that $\tau_k = \tau$ for all k , and orthogonal training sequences $\{s_k(q)\}$ are employed, the estimation problem (4) becomes separable in nodes k . However, when relative timing offsets are present, multiuser interference between sensor waveforms necessitates exponentially complex in N_s joint optimization to obtain the maximum-likelihood solution.

To obtain a practical algorithm in reconfigurable hardware, we propose to approximate (4) using the Generalized Successive Interference Cancellation approach in [4]. Note that stage 1 of GSIC corresponds to N_s independent correlations and is thus optimal for synchronized nodes and orthogonal sequences. Thus we can balance levels of cancellation and hardware complexity to obtain a feasible collector estimation algorithm. At iteration k of GSIC, a cancelled signal matrix $\mathbf{R}^k$ is available. The ML joint estimates of $\delta\omega_l, \tau_l, \mathbf{h}_l$ are then computed for $l \in \{1, \dots, N_s\} \setminus \{p_1, \dots, p_{k-1}\}$, where p_k is the sensor index selected on GSIC iteration k . The index p_k is chosen from the joint estimates $\hat{\delta\omega}_l, \hat{\tau}_l, \hat{\mathbf{h}}_l$ that best fit the residual $\mathbf{R}^k$. The residual $\mathbf{R}^{k+1}$ is then updated using the cancellation

$$\mathbf{R}^{k+1} = \mathbf{R}^k - \sum_{q=0}^{N_c-1} \mathbf{p}_q(\hat{\tau}_{p_k}, \hat{\delta\omega}_{p_k}) \hat{\mathbf{h}}_{p_k}^T s_{p_k}(q). \quad (5)$$

The key step in GSIC is finding the intermediate estimates in indices l . These are defined at iteration k by

$$\hat{\tau}_l, \hat{\delta\omega}_l, \hat{\mathbf{h}}_l = \arg \min_{\tau_l, \delta\omega_l, \mathbf{h}_l} \|\mathbf{R}^k - \sum_{q=0}^{N_c-1} \mathbf{p}_q(\tau_l, \delta\omega_l) \mathbf{h}_l^T s_l(q)\|_F^2. \quad (6)$$

The channel estimate $\hat{\mathbf{h}}_l$ conditioned on $\tau_l, \delta\omega_l$ is readily shown to equal

$$\begin{aligned} \hat{\mathbf{h}}_l = & \quad (7) \\ & \frac{1}{\sum_{q=0}^{N_c-1} \|\mathbf{p}_q(\tau_l, \delta\omega_l)\|^2 |s_l(q)|^2} \sum_{q=0}^{N_c-1} (\mathbf{R}^k)^T \mathbf{p}_q(\tau_l, \delta\omega_l)^* s_l(q)^*. \end{aligned}$$

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Initialize  $\mathbf{R}^1 = \mathbf{R}(m)$ 
For  $k = 1, 2, \dots, N_s$ 
  For  $l = 1, \dots, N_s \setminus \{p_1, \dots, p_{k-1}\}$ 
     $\hat{\tau}_k, \hat{\delta\omega}_l = \arg \max_{\tau_l, \delta\omega_l} \gamma_l(\tau_l, \delta\omega_l)$  where
     $\gamma_l(\tau_l, \delta\omega_l) = \frac{\left\| \sum_{q=0}^{N_c-1} (\mathbf{R}^k)^T \mathbf{p}_q^*(\tau_l, \delta\omega_l) s_l(q)^* \right\|^2}{\sum_{q=0}^{N_c-1} \|\mathbf{p}_q(\tau_l, \delta\omega_l)\|^2 |s_l(q)|^2}$ 
  Next  $l$ 
   $p_k = \arg \max_l \gamma(\hat{\tau}_l, \hat{\delta\omega}_l)$ 
   $\hat{\mathbf{h}}_{p_k} = \frac{\sum_{q=0}^{N_c-1} (\mathbf{R}^k)^T \mathbf{p}_q(\hat{\tau}_{p_k}, \hat{\delta\omega}_{p_k})^* s_{p_k}(q)^*}{\sum_{q=0}^{N_c-1} \|\mathbf{p}_q(\hat{\tau}_{p_k}, \hat{\delta\omega}_{p_k})\|^2 |s_{p_k}(q)|^2}$ 
   $\mathbf{R}^{k+1} = \mathbf{R}^k - \sum_{q=0}^{N_c-1} \mathbf{p}_q(\hat{\tau}_{p_k}, \hat{\delta\omega}_{p_k}) \hat{\mathbf{h}}_{p_k}^T s_{p_k}(q)$ 
Next  $k$ 

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TABLE I

GSIC ALGORITHM FOR JOINT CHANNEL/DELAY/OFFSET ESTIMATION – TRAINING

It is assumed that the raised-cosine pulse vectors are approximately orthogonal for minimal excess bandwidth. That is $\mathbf{p}_q(\tau_l, \delta\omega_l)^H \mathbf{p}_{q'}(\tau_l, \delta\omega_l) \approx \frac{2E_s}{N_u T_s} \delta_{q,q'}$. Inserting the conditional estimate from (7) and employing the pulse vector orthogonality in (6) gives the estimates for delay and offset.

$$\hat{\tau}_l, \hat{\delta\omega}_l = \arg \max_{\tau_l, \delta\omega_l} \frac{\left\| \sum_{q=0}^{N_c-1} (\mathbf{R}^k)^T \mathbf{p}_q^*(\tau_l, \delta\omega_l) s_l(q)^* \right\|^2}{\sum_{q=0}^{N_c-1} \|\mathbf{p}_q(\tau_l, \delta\omega_l)\|^2 |s_l(q)|^2}. \quad (8)$$

The GSIC algorithm for training symbols is summarized in Table I.

IV. HYBRID ANALYSIS/SIMULATION OF COOPERATIVE MIMO BER

The error rate for MIMO systems is usually evaluated based on averaging bounds for pairwise error probability (PEP) w.r.t. circular Gaussian statistics for the channel $\{\mathbf{h}_k\}$ [7][8]. However, the channel/offset estimation errors in GSIC are difficult to characterize analytically, and thus we pursue a hybrid analysis/simulation approach. Linear decoding is assumed, which is optimal only under perfect uplink synchronization and pulse orthogonality [5]. Nevertheless, we employ linear decoding here as (a) it is a pragmatic solution for reconfigurable hardware implementation and (b) it leads to closed-form conditional BER expressions. An analytic formula for BER P_b is obtained conditioned on simulated values of $\{\tau_k, \delta\omega_k, \mathbf{h}_k\}$ and their corresponding estimates, thus obtaining a closed-form solution for $P_b(n)$ at each simulation iteration. Time-averaging of $P_b(n)$ leads to an estimate of unconditional BER, assuming ergodicity of the channel/offsets and estimation errors.

The linear decoder is derived using the received signal (2) for QPSK modulation. Following [5], define a mapping from information symbols b_l to code symbols $s_k(q)$ that leads to a linear decoding rule. Let $k_q(l)$ for $q = 0, \dots, N_c - 1$ be the indices such that $s_{k_q(l)}(q) \in \{\pm b_l, \pm b_l^*\}$. That is, at time q ,

sensor $k_q(l)$ transmits the symbol $\pm b_l^{(*)}$. Also define sufficient statistics for decoding as

$$\mathbf{y}_k(q) = \hat{\mathbf{h}}_k^T \mathbf{R}(m)^H \mathbf{p}_q(\hat{\tau}_k, \hat{\delta\omega}_k) \quad (9)$$

$$Q_{k,k',q,q'} = \mathbf{p}_{q'}(\hat{\tau}_{k'}, \hat{\delta\omega}_{k'})^H \mathbf{p}_q(\hat{\tau}_k, \hat{\delta\omega}_k) \hat{\mathbf{h}}_k^H \hat{\mathbf{h}}_{k'}.$$

Also let modified sufficient statistics be defined by

$$y'_{k_q(l)}(q) = \begin{cases} (-)y_{k_q(l)}(q) & \text{if } s_{k_q(l)}(q) = (-)b_l \\ (-)y_{k_q(l)}(q)^* & \text{if } s_{k_q(l)}(q) = (-)b_l^* \end{cases} \quad (10)$$

Linear decoding is only optimum when reception from the sensors is synchronous with $\tau_k = 0$ for all k , and orthogonal pulses $\mathbf{p}_q$. The resulting decoder for QPSK is

$$\hat{b}_l = \arg \max_{b_l} 2Re \left\{ b_l \sum_{q=0}^{N_c-1} y'_{k_q(l)}(q) \right\} - |b_l|^2 \sum_{q=0}^{N_c-1} Q_{k_q(l),k_q(l),q,q}. \quad (11)$$

The linear decoder (11) is employed here for the imperfect synchronization/estimation case as well. For QPSK modulation, the BER is then obtained in closed form. Denote the combination of estimated carrier offset and delay as $\hat{\theta}_k = \{\hat{\tau}_k, \hat{\delta\omega}_k\}$. The decision variable for the bit $Re\{b_1\} = 1$ becomes

$$U_1 = 2Re \left\{ \sum_{q=0}^{N_c-1} y'_{k_q(1)}(q) \right\},$$

$$= 2Re \left\{ \sum_{q=0}^{N_c-1} \text{sgn}(Re\{s_{k_q(1)}\}) \hat{\mathbf{h}}_{k_q(1)}^T \mathbf{R}^H \mathbf{p}_q(\hat{\theta}_{k_q(1)}) \right\}. \quad (12)$$

The BER corresponding to the decision variable U_1 , conditioned on the channel/estimate trajectory, is readily shown to equal

$$P_b = \frac{1}{2^{2N_s-1}} \sum_{S^n: \text{sgn}(Re\{b_1^n\})=1} \frac{1}{2} \text{erfc} \left(\frac{E\{U_1^n\}}{\sqrt{2Var\{U_1\}}} \right),$$

$$E\{U_1^n\} =$$

$$2Re \left\{ \sum_{q=0}^{N_c-1} \text{sgn}(Re\{s_{k_q(1)}^n\}) \hat{\mathbf{h}}_{k_q(1)}^T (S^n)^H \mathbf{p}_q(\hat{\theta}_{k_q(1)}) \right\}. \quad (13)$$

The noiseless received signal matrix S^n corresponds to the n -th of 4^{N_s} OSTBC codewords, and is defined by

$$S^n = \sum_{k=1}^{N_s} \sum_{q=0}^{N_c-1} \mathbf{p}_q(\tau_k, \delta\omega_k) \hat{\mathbf{h}}_k^T s_k^n(q). \quad (14)$$

The variance term in (13) is

$$Var\{U_1\} =$$

$$\frac{4N_0}{T_s} \sum_{q=0}^{N_c-1} \sum_{q'=0}^{N_c-1} \hat{\mathbf{h}}_{k_q(1)}^H \hat{\mathbf{h}}_{k_{q'}(1)} \mathbf{p}_q(\hat{\theta}_{k_q(1)})^H \mathbf{p}_{q'}(\hat{\theta}_{k_{q'}(1)}). \quad (15)$$

V. HARDWARE DESIGN

Applying an OSTBC to a distributed array of sensors represents a significant advancement in complexity in terms of the communications protocol and link setup. Naturally, the hardware design must be able to provide the needed feature set in order to implement such an architecture. The two principle considerations are timing and frequency offsets.

Obviously, if there is poor time synchronization then the sensor OSTBC signals will not be time-aligned at the collector, resulting in a loss of orthogonality and the introduction of inter-symbol interference (ISI). The timing problem is dealt with by using a high oversampling rate for good delay resolution, and downlink timing control. The GSIC-derived delay estimates are then used to calculate the appropriate sensor symbol clock corrections. Alternatively, a common synchronization beacon can be used; this can be sent by either the collector or a local sensor node. In either case, oversampling rates of $N_d \geq 16$ are needed in order to maintain timing synchronization. Alternative techniques, such as the use of the global positioning system (GPS), have been explored but lack the fidelity for the target rates of our hardware.

The complexity of the joint frequency-offset estimation problem is driven by the absolute maximum offset between the sensor node and collector, level of fidelity, and number of sensor nodes. Driving the overall design is the maximum frequency offset level for which we must compensate. Our RF design offers a production capable 0.5 parts per million (PPM) maximum offset at the carrier frequency with a maximum of 4.5 PPM after ten years of operation. Thus, while we will typically encounter offsets that are a maximum of 1 kHz, we must be able to provide compensation for up to 10 kHz over the life of the equipment. These considerations, and the required fidelity of the tolerable frequency offset in channel tracking, drive the required search range of our frequency offset estimation.

The overall architecture of the collector demodulation is shown in Figure 2. In terms of the GSIC algorithm, our primary area of consideration is the timing and frequency estimation block. The collector antennas are co-located and hence have high correlation in their receive channel statistics. Furthermore, the separate collector RF sections are driven by a single VCO meaning the relative offsets at each collector antenna are the same. In Tables II and III we show the relative resource use and power consumption for the different portions of our FPGA baseband processing design. Note that a 50 MHz clock speed is used. The most expensive portion of the design is the single-stage GSIC (correlation method without cancellation), which provides timing and frequency offset estimates. This process involves a sample-by-sample multiplication with the training sequence and then an FFT. The output of the FFT provides an indication of the degree to which the received signal is correlated with the training sequence (indicating timing) as well as the frequency (indicating offset).

The primary operation in GSIC is the correlation/FFT operation. From Table I, the columnwise correlations of $\mathbf{R}$

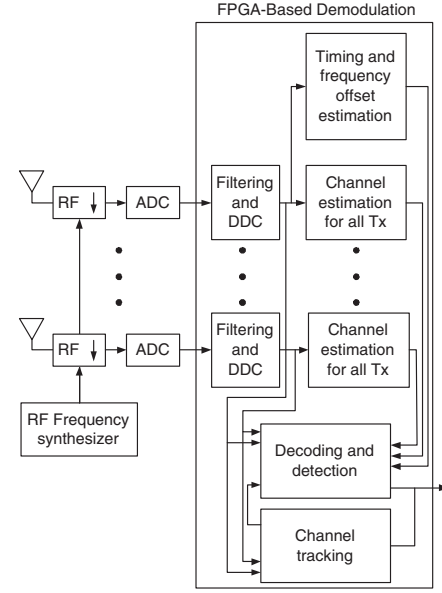


Fig. 2. Collector demodulation architecture.

can be written as (Matlab notation)

$$\mathbf{R}(:, i)^T \mathbf{p}_q^*(\tau_l, \delta\omega_l) = \sum_{m=0}^{N_c N_d - 1} \mathbf{R}(m, i) s_l(mT_s - \tau_l) e^{-i2\pi\delta\omega_l mT_s}, \quad (16)$$

where $s_l(mT_s - \tau_l) = \sum_{q=0}^{N_c-1} s_l(q)p(mT_s - qT - \tau_l)$ is the effective training sequence modulated by the pulse function. By quantizing $\delta\omega_l$ to the integer FFT frequencies and zero padding if necessary, (16) is (a) the Hadamard product of the received samples per antenna with the training sequence $s_l(mT_s)$ followed by an FFT which simultaneously performs the required correlation. We note that the throughput of the overall design is constrained by the FFT operation as it must operate at the oversampled rate, whereas all other portions of the design operate at the symbol rate. There is a trade-off in terms of latency (throughput) versus resource use in the FFT. That is, if higher degrees of parallelism are used then there is a throughput increase, with the corresponding requirement of additional hardware resources.

VI. RESULTS AND CONCLUSIONS

The analysis/simulation error rate approximation (13) was computed for cases of (a) $N_s = 2$ sensors using the Alamouti code and (b) $N_s = 4$ sensors using $\mathcal{G}_c^4$ in [5]. A collector with $M_c = 4$ antennas was used for both codes. In addition to GSIC estimation, a correlation method was also employed. Correlation corresponds to the first GSIC iteration only and thus excludes subsequent cancellation steps. At each simulation iteration, a channel/offset estimate was computed based on $N_c = 63$ length quasi-orthogonal Gold sequences transmitted by each sensor. The channels $\{\mathbf{h}_k\}$ were generated independently on each iteration as circular Gaussian with unit-variance elements. The conditional BER (13) was then time-

	Area					Performance (ns)	Power (mw)
	FFs 40960	LUTs 40960	SLICES 20480	BRAMs 40	MULTIPLIERS 40	N/A	N/A
Transceiver (Top Level)	13690	7433	9405	14	22	19.57	202.35
DDC	1247	892	750	0	0	8.27	8.01
Detection/Downsample Channel Correction	9649	5795	7047	12	12	18.66	145.14
Channel Tracking	2313	2201	1397	0	0	12.86	33.02
DUC	2280	1755	1408	2	10	10.87	39.87

TABLE II
RESOURCE USE AND POWER CONSUMPTION FOR XC3S2000-5FG676 SPARTAN-3 FPGA.

Area					Performance (ns)	Power (mw)
FFs 21504	LUTs 21504	SLICES 10752	BRAMs 56	MULTIPLIERS 56	N/A	N/A
13690	8155	9483	14	22	17.28	572.58
1247	892	750	0	0	5.39	27.29
9649	5907	7103	12	12	15.21	389.32
2213	2225	1403	1	0	9.21	84.51
2280	1731	1410	2	10	7.97	99.12

TABLE III
RESOURCE USE AND POWER CONSUMPTION FOR XC2V2000-6FG676 VIRTEX-II FPGA.

averaged over channel and estimator realizations to obtain the final unconditional BER.

Fig. 3 shows the analysis/simulation BER estimates. For known CSI, $\mathcal{G}_c^4$ 4x4 code performance is 3.5 dB better than Alamouti 2x4 at 10^{-4} SER. This performance gain is due to (a) increased transmit diversity gain of $\mathcal{G}_c^4$, and (b) A 3 dB increase in E_s for the 4x4 code over the Alamouti code (2x4), since the individual sensor transmit power is the same for both schemes. With GSIC estimation, $\mathcal{G}_c^4$ performance is still > 2.5 dB better at a 10^{-4} BER than Alamouti 2x4. The frequency offset estimation error was also computed in the simulation corresponding to Fig. 3. At $E_b/N_0 = 0$ dB, GSIC for $\mathcal{G}_c^4$ yielded a 200 Hz lower average offset error than the correlation method.

To conclude, GSIC appears to be a practical solution to the joint channel/offset/delay estimation problem in cooperative MIMO sensor networks. Improvements to the GSIC approach yielding higher computational efficiency, and further optimization of codes and training sequences should be investigated.

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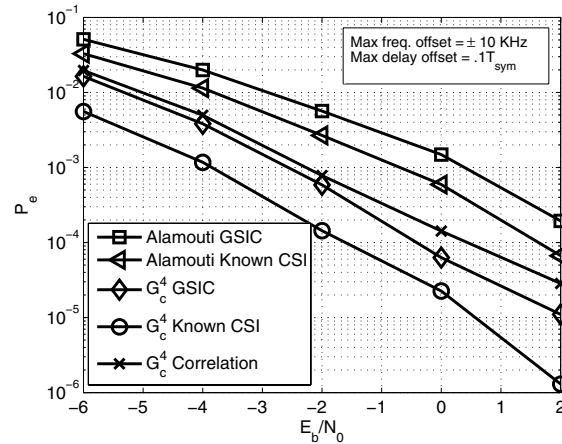


Fig. 3. Analysis/Simulation BER results for GSIC and Correlation.

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