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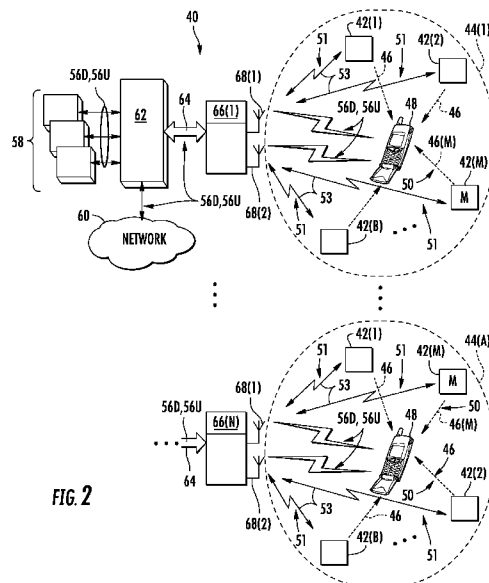
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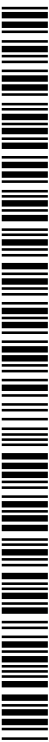
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(54) Title: ULTRASOUND-BASED LOCALIZATION OF CLIENT DEVICES WITH INERTIAL NAVIGATION SUPPLEMENT IN DISTRIBUTED COMMUNICATION SYSTEMS AND RELATED DEVICES AND METHODS



(57) Abstract: Spatially located ultrasound beacons (42(1), 42(2)...) are provided in known locations within a distributed communication system (40). The ultrasound beacons are configured to emit ultrasound pulses (46) that can be received by client devices (48) in ultrasound communication range of the beacons. The client devices are configured to analyze the received ultrasound pulses from the beacons to determine their time-difference of arrival and as a result, their location(s) within the distributed communication system. The client devices comprise inertial navigation systems (INS) that calculate client device location as the client device moves, and when received ultrasound signals are below a predefined threshold.



**ULTRASOUND-BASED LOCALIZATION OF CLIENT DEVICES WITH INERTIAL
NAVIGATION SUPPLEMENT IN DISTRIBUTED COMMUNICATION SYSTEMS AND
RELATED DEVICES AND METHODS**

PRIORITY APPLICATION

[0001] The present application claims the benefit of priority under 35 U.S.C. § 119 of U.S. Provisional Patent Application No. 61/652,575, filed on May 29, 2012, the content of which is relied upon and incorporated herein by reference in its entirety.

BACKGROUND

Field of the Disclosure

[0002] The technology of the disclosure relates to distributed communication systems, and in particular to providing devices, systems, and methods to allow determination of the location of client devices within distributed communication systems.

Technical Background

[0003] Wireless communication is rapidly growing, with ever-increasing demands for high-speed mobile data communication. “Wireless fidelity” or “WiFi” systems and wireless local area networks (WLANs) are now deployed in many different types of areas. Distributed antenna systems communicate with wireless devices called “clients,” “client devices,” or “wireless client devices,” which must reside within the wireless range or “cell coverage area,” to communicate with an access point device. Distributed antenna systems are particularly useful inside buildings or other indoor environments where client devices may not otherwise effectively receive radio frequency (RF) signals from a source.

[0004] Distributed antenna or distributed communication systems have RF antenna coverage areas, also referred to as “antenna coverage areas.” Antenna coverage areas can have a relatively short range - from a few meters up to twenty meters. Combining a number of access point devices creates an array of antenna coverage areas. Because the antenna coverage areas each cover small areas, there are typically only a few client devices per coverage area. This minimizes the amount of bandwidth shared among the wireless system users. Typical indoor distributed communication systems include a central or head-end unit communicatively coupled to a plurality of remote units that each provides an antenna coverage area. The remote units each include RF transceivers coupled to an antenna to transmit communication signals (e.g., RF, data) wirelessly. The remote units are coupled to

the head-end station via communication media to receive downlink communication signals to be wirelessly transmitted over an antenna in the coverage area to client devices. The remote units also wirelessly receive uplink communication signals from client devices to be communicated to the head-end station.

[0005] FIG. 1 is a schematic diagram of an optical fiber-based distributed communication system 10. The system 10 is configured to create one or more antenna coverage areas for establishing communication with wireless client devices (sometimes referred to herein as mobile terminals) located in the RF range of the antenna coverage areas. The system 10 includes a central unit or head-end unit (HEU) 12, one or more remote antenna units (RAUs) 14 and an optical fiber link 16 that optically couples the HEU 12 to the RAU 14. The HEU 12 is configured to receive communication over downlink electrical RF signals 18D from a source or sources, such as a network or carrier, and provide such communication to the RAU 14. Such downlink communication signals are received through a conventional input, such as a downlink input. If multiple sources are present, there may be multiple downlink inputs. The HEU 12 is also configured to return communication received from the RAU 14, via uplink electrical RF signals 18U, back to the sources. The optical fiber link 16 includes at least one downlink optical fiber 16D to carry signals communicated from the HEU 12 to the RAU 14 and at least one uplink optical fiber 16U to carry signals communicated from the RAU 14 back to the HEU 12. An interface couples the HEU 12 to the optical fiber link 16. The interface may be a conventional interface configured to receive downlink communication signals and pass the downlink communication signals to the RAU 14 through the link 16.

[0006] The system 10 has an antenna coverage area 20 that can be substantially centered about the RAU 14. The antenna coverage area 20 of the RAU 14 forms an RF coverage area 22. The HEU 12 is adapted to perform any one of a number of Radio-over Fiber (RoF) applications, such as radio-frequency identification (RFID), WLAN communication, or cellular phone service. Shown within the antenna coverage area 20 is a client device 24 in the form of a mobile terminal as an example, which may be a cellular telephone, smart phone, tablet computer, or the like. The client device 24 can be any device that is capable of receiving RF communication signals. The client device 24 includes an antenna 26 (e.g., a bipole, monopole, bowtie, inverted F, a wireless card, or the like) adapted to receive and/or send electromagnetic RF signals.

[0007] The HEU 12 includes an electrical-to-optical (E/O) converter 28 to communicate the electrical RF signals over the downlink optical fiber 16D to the RAU 14, to in turn be

communicated to the client device **24** in the antenna coverage area **20** formed by the RAU **14**. The E/O converter **28** converts the downlink electrical RF signals **18D** to downlink optical RF signals **30D** to be communicated over the downlink optical fiber **16D**. The RAU **14** includes an optical-to-electrical (O/E) converter **32** to convert received downlink optical RF signals **30D** back to electrical signals to be communicated wirelessly through an antenna **34** of the RAU **14** to client devices **24** located in the antenna coverage area **20**.

[0008] The antenna **34** receives wireless RF communication from client devices **24** and communicates electrical RF signals representing the wireless RF communication to an E/O converter **36** in the RAU **14**. The E/O converter **36** converts the electrical RF signals into uplink optical RF signals **30U** to be communicated over the uplink optical fiber **16U**. An O/E converter **38** in the HEU **12** converts the uplink optical RF signals **30U** into uplink electrical RF signals, which are then communicated as uplink electrical RF signals **18U** back to a network.

[0009] As noted above, it may be desired to provide the distributed communication system **10** in **FIG. 1** indoors, such as inside a building or other facility. Other services may be negatively affected or not possible due to the indoor environment. For example, it may be desired or required to provide localization services for the client devices **24**, such as emergency 911 (E911) services. If a client device is located indoors, techniques such as global positioning services (GPS) may not be effective at providing or determining the location of the client device. Indoors, GPS signals are usually too weak to be received by client devices. Further, triangulation and/or trilateration techniques from the outside network may not be able to determine the location of client devices.

[0010] Other methods for determining location of client devices may be based on receiving wireless data signals transmitted by existing wireless data devices provided in wireless communication systems (e.g., cell phone network and/or WLAN access points). However, use of existing wireless data signals may only be accurate to down to a resolution of still a relatively large distance (e.g., ten meters) since the client devices may receive wireless data signals from wireless data devices not in close proximity to the client devices. Further, use of existing wireless data signals for localization may necessitate a greater density of RF communication devices than is required for data communication. Thus, determining location of client devices at lower resolution distances (e.g., less than ten (10) meters, floor level in a building, etc.) using wireless communication signals transmitted from existing wireless data devices may not be possible without providing additional, greater densities of these wireless data devices at greater cost and complexity.

SUMMARY OF THE DETAILED DESCRIPTION

[0011] Embodiments disclosed herein include ultrasound-based localization of client devices in distributed communication systems. Related devices, systems, and methods are also disclosed. In embodiments disclosed herein, a plurality of spatially located ultrasound beacons are provided in known locations within the distributed communication systems. Each of the spatially located ultrasound beacons is configured to emit ultrasound pulses that can be received by client devices in ultrasound communication range of the ultrasound beacons. The client devices are configured to analyze the received ultrasound pulses from the plurality of ultrasound beacons to determine their time-difference of arrivals at the client device. As a result, the client devices can determine their relative distance to ultrasound beacons in a distributed communication system. In certain embodiments, a master ultrasound beacon is provided that encodes location information in a second channel with emitted ultrasound pulses received by the client devices that can be used with the determined relative distance to determine location of the client device in the distributed communication system.

[0012] The distributed communication systems employing ultrasound beacons can facilitate the determining and/or providing of location information to client devices, including wireless client devices that may not otherwise be able to receive, for example, GPS information from GPS satellites. Providing location information to client devices inside a building or other location may make location-based services possible (e.g., emergency 911 (E911) services) for the client devices.

[0013] Use of ultrasound pulses by a client device to determine its location in a distributed communication system can provide greater resolution (e.g., sub-meter resolution) in location determination. Increased resolution results from the lower velocity of sound (as opposed to light or radio-frequency signals), which translates into lessened requirements for time resolution in ultrasound pulse measurements. Ultrasound waves experience strong attenuation in buildings walls, ceilings, and floors, thus the ultrasound beacons can be strategically placed to allow client devices to avoid detection of ultrasound waves from other ultrasound beacons not located in proximity to the client devices (e.g., on a different floor). Use of ultrasound pulses to facilitate location determination using time-difference of arrival can also avoid the need to synchronize the clock of the client device.

[0014] In one embodiment, an ultrasound beacon for facilitating client devices determining their location in a distributed communication system comprises a controller, and an ultrasound emitter coupled to the controller, the ultrasound emitter configured to emit

ultrasound pulses over at least one speaker. The ultrasound beacon also comprises a radio-frequency (RF) receiver coupled to the controller, the RF receiver configured to receive RF synchronization signals comprising synchronization information. The controller is configured to synchronize an internal clock based on the received synchronization information, and to cause the ultrasound emitter to emit ultrasound pulses in synchronization based on the synchronization information with other ultrasound beacons among an ultrasound beacon cluster, to client devices located in the distributed communication system.

[0015] In another embodiment, a client device configured to communicate in a distributed communication system comprises a controller, and an ultrasound receiver coupled to the controller. The ultrasound receiver is configured to receive ultrasound pulses over at least one microphone. The client device also comprises a radio-frequency (RF) transceiver coupled to the controller, the RF transceiver configured to wirelessly receive and transmit RF communication signals over at least one antenna. The client device also comprises an inertial navigation system (INS) operatively coupled to the controller. The controller is configured to calculate a position using received ultrasound signals, and use the INS to calculate a second position from the first position when the received ultrasound signals are below a predefined threshold.

[0016] In another embodiment, a method of a RF communication client device configured to communicate in a distributed communication system determining location within the distributed communication systems is provided. The method comprise calculating a first position using ultrasound signals received at the client device and calculating a second position using an inertial navigation system within the client device when a signal strength of the ultrasounds signals falls below a predefined threshold.

[0017] Additional features and advantages will be set forth in the detailed description which follows, and in part will be apparent to those skilled in the art from that description or recognized by practicing the embodiments as described herein, including the detailed description that follows, the claims, as well as the appended drawings.

[0018] It is to be understood that both the foregoing general description and the following detailed description present embodiments, and are intended to provide an overview or framework for understanding the nature and character of the disclosure.

[0019] The drawings illustrate various exemplary embodiments, and together with the description serve to explain the principles and operation of the concepts disclosed.

BRIEF DESCRIPTION OF THE FIGURES

[0020] FIG. 1 is a schematic diagram of an exemplary optical fiber-based distributed communication system;

[0021] FIG. 2 is a schematic diagram of a distributed communication system employing a plurality of ultrasound beacons organized in ultrasound beacon clusters and configured to emit ultrasound pulses to be received by client devices to determine their location(s);

[0022] FIG. 3 is a schematic diagram of a distributed communication system employing ultrasound beacon clusters in different floors of a building;

[0023] FIG. 4 is a flowchart illustrating a process of an ultrasound beacon receiving radio-frequency (RF) signals including synchronization information used by ultrasound beacons to synchronize their internal clocks used to control ultrasound pulse emission;

[0024] FIG. 5 is a schematic diagram of an ultrasound beacon that can be employed in the distributed communication system in FIG. 2, wherein the ultrasound beacon may be a master ultrasound beacon or a non-master ultrasound beacon;

[0025] FIG. 6 is a flowchart illustrating a process of an ultrasound beacon emitting ultrasound pulses to be received by client devices, which can be used by the client devices to determine their location in a distributed communication system;

[0026] FIGS. 7A and 7B are flowcharts illustrating a process of a client device receiving ultrasound pulses from ultrasound beacons and the client devices using the time-difference-of-arrival of the received ultrasound pulses to device determine location;

[0027] FIG. 8 is a schematic diagram of a client device configured with an ultrasound receiver configured to receive ultrasound pulses and/or location information encoded in ultrasound pulses emitted by ultrasound beacons in a distributed communication system;

[0028] FIG. 9 is a schematic diagram illustrating ultrasound beacons, which may be the exemplary ultrasound beacon in FIG. 4, included in remote units in a distributed communication system, which may be the system in FIG. 2;

[0029] FIG. 10 illustrates an ultrasound cluster with only two ultrasound beacons according to an exemplary embodiment of the present disclosure;

[0030] FIG. 11 is a flowchart illustrating alternate position calculation procedures;

[0031] FIG. 12 is a schematic diagram of an alternate distributed communication system having a supplementary ultrasound system; and

[0032] FIG. 13 is a flowchart illustrating an alternate embodiment of position calculation procedures for a system using a supplementary ultrasound system.

DETAILED DESCRIPTION

[0033] Embodiments disclosed herein include ultrasound-based localization of client devices in distributed communication systems, and related devices, systems, and methods. Ultrasound is sound at one or more wave frequencies higher than what humans can hear. The upper frequency limit of human hearing is different for different individuals and decreases with increasing age. For example, the lower limit of ultrasound wave frequencies may be approximately 16 KHz or 20 KHz. Ultrasound pulses are bursts of ultrasound waves. Client devices are configured to analyze the received ultrasound pulses from the plurality of ultrasound beacons to determine their time-difference of arrivals at the client device. As a result, the client devices can determine their relative distance to ultrasound beacons in a distributed communication system. In certain embodiments, a master ultrasound beacon is provided that encodes location information in a second channel with emitted ultrasound pulses received by the client devices that can be used with the determined relative distance to determine location of the client device in the distributed communication system. The client devices may comprise inertial navigation systems (INS) that calculate client device location as the client device moves, and when received ultrasound signals are below a predefined threshold.

[0034] In this regard, **FIG. 2** is a schematic diagram of an exemplary distributed communication system **40** employing a plurality of ultrasound beacons **42** organized in ultrasound beacon clusters **44**. The ultrasound beacons **42** are configured to emit ultrasound pulses **46** to be received by client devices **48** in the distributed communication system **40**. The distributed communication system **40** may be provided indoors in a building or other structure where it is difficult or impossible for the client device **48** to receive global positioning system (GPS) signals to determine location. In this example, a plurality of ultrasound beacon clusters **44(1)-44(A)** are provided, wherein 'A' can be any positive whole integer. Each ultrasound beacon cluster **44(1)-44(A)** includes a plurality of non-master ultrasound beacons **42(1)-42(B)** and one master ultrasound beacon **42(M)** in this example, wherein 'B' can be any positive whole integer.

[0035] With continuing reference to **FIG. 2** and as will be discussed in more detail below, the master ultrasound beacons **42(M)** are configured to encode as location information **50**, their location and the location of the other ultrasound beacons **42(1)-42(B)** in their ultrasound beacon cluster **44** with the ultrasound pulses **46(M)** emitted to the client devices **48**. The client devices **48** receive ultrasound pulses **46** from other ultrasound beacons **42(1)-42(B)**. The client devices **48**, equipped with a microphone to detect the ultrasound pulses **46**

and other components, are configured to determine their location using the received location information **50** and determining the time-difference-of-arrival between the different received ultrasound pulses **46, 46(M)**. The client devices **48** use time-difference-of-arrival analysis to determine their location relative to the master ultrasound beacon **42(M)** and the non-master ultrasound beacons **42(1)-42(B)** in the distributed communication system **40**. The determined location of the client devices **48** can be provided to another device or network for any purpose desired.

[0036] With continuing reference to **FIG. 2** and as will also be discussed in more detail below, the ultrasound beacons **42(1)-42(B), 42(M)** are also capable of receiving synchronization information **51** over received communication signals or synchronization signals, which are RF synchronization signals **53** in this example. The synchronization signals could be provided by other communication methods or mediums. For example, the synchronization signals could be provided as described in U.S. Patent No. 8,175,649 entitled METHOD AND SYSTEM FOR REAL TIME CONTROL OF AN ACTIVE ANTENNA OVER A DISTRIBUTED ANTENNA SYSTEM, which is hereby incorporated by reference in its entirety. In this example, the RF synchronization signals **53** can be distributed by the remote units **66(1)-66(N)** in the distributed communication system **40** to the ultrasound beacons **42(1)-42(B), 42(M)** as one convenient method. Regardless of the distribution method of the RF synchronization signals **53**, the synchronization information **51** is used by the ultrasound beacons **42(1)-42(B), 42(M)** to synchronize their internal clocks used to control emission of the ultrasound pulses **46, 46(M)**. In this manner, the client devices **48** can distinguish between ultrasound pulses **46, 46(M)** received from different ultrasound beacons **42(1)-42(B), 42(M)** to analyze their time-difference-of-arrivals to determine location. By synchronizing the ultrasound beacons **42(1)-42(B), 42(M)**, the client devices **48** do not have to be synchronized with the ultrasound beacons **42(1)-42(B), 42(M)**.

[0037] With continuing reference to **FIG. 2**, note that different numbers of ultrasound beacons **42** can be provided in different ultrasound beacon clusters **44(1)-44(A)** as long as at least one master ultrasound beacon **42(M)** and a plurality of other non-master ultrasound beacons **42(1)-42(B)** are provided in each ultrasound beacon cluster **44(1)-44(A)**. The ultrasound beacon clusters **44(1)-44(A)** may be arranged in the distributed communication system **40** such that a client device **48** can receive ultrasound pulses **46** only from ultrasound beacons **42** in one ultrasound beacon cluster **44(1)-44(A)** for a given location of the client device **48**. This limitation can be provided as range limitations by placement of the ultrasound beacon clusters **44(1)-44(A)** with respect to each other and/or differences in

carrier frequencies as non-limiting examples. In this manner, the client device 48 does not receive ultrasound pulses 46 from two different ultrasound beacon clusters 44(1)-44(A) that cannot be compared in a time-difference-of-arrival analysis for a given location of the client device 48. Also, the client device 48 would not receive location information 50 from multiple master ultrasound beacons 42(M) in a given location of the client device 48.

[0038] For example, as illustrated in FIG. 3, the distributed communication system 40 may be provided in a building infrastructure 52. The ultrasound beacon clusters 44(1)-44(A) may be on each floor of a building infrastructure 52. For example, the ultrasound beacon cluster 44(1) may be provided on a first floor 54(1) of the building infrastructure 52. The ultrasound beacon cluster 44(2) may be provided on a second floor 54(2) of the building infrastructure 52. The ultrasound beacon cluster 44(3) may be provided on the third floor 54(3) of the building infrastructure 52.

[0039] With reference to FIGS. 2 and 3, the ultrasound beacon clusters 44(1)-44(A) are configured to be provided in the distributed communication system 40 that is also configured to downlink and uplink distributed communication signals 56D, 56U from base stations 58 and/or a network 60 to and from the client device 48. In this regard, a central unit 62 is provided that is configured to receive downlink communication signals 56D from the base station(s) 58 and/or the network 60 for distribution of a communication media 64 to one or more remote units 66(1)-66(N). The remote units 66(1)-66(N) include at least one RF antenna 68(1), 68(2) configured to radiate the downlink communication signals 56D to the client devices 48. Multiple RF antennas 68(1), 68(2) may be provided for multiple input, multiple output (MIMO) communication. The remote units 66(1)-66(N) are also configured to receive uplink communication signals 56U from the client devices 48 to be distributed over the communication media 64 to the central unit 62 to be provided to the base station(s) 58 and/or the network 60.

[0040] With continuing references to FIGS. 2 and 3, the communication media 64 in the distributed communication system 40 could be one or a plurality of communication medium, and/or any of different types. For example, the communication media 64 may be electrical conductors, such as twisted-pair wiring or coaxial cable. Frequency division multiplexing (FDM) or time division multiplexing (TDM) can be employed to provide the downlink and uplink communication signals 56D, 56U between the central unit 62 and the remote units 66(1)-66(N). Alternatively, separate, dedicated communication media 64 may be provided between the central unit 62 and the remote units 66(1)-66(N). Further, the downlink and uplink communication signals 56D, 56U could include digital data signals and/or RF

communication signals.

[0041] Examples of digital data services provided with digital data signals include, but are not limited to, Ethernet, WLAN, WiMax, WiFi, Digital Subscriber Line (DSL), and LTE, etc. Ethernet standards could be supported, including but not limited to 100 Megabits per second (Mbps) (i.e., fast Ethernet) or Gigabit (Gb) Ethernet, or ten Gigabit (10G) Ethernet. Examples of RF communication services provided with RF communication signals include, but are not limited to, US FCC and Industry Canada frequencies (824-849 MHz on uplink and 869-894 MHz on downlink), US FCC and Industry Canada frequencies (1850-1915 MHz on uplink and 1930-1995 MHz on downlink), US FCC and Industry Canada frequencies (1710-1755 MHz on uplink and 2110-2155 MHz on downlink), US FCC frequencies (698-716 MHz and 776-787 MHz on uplink and 728-746 MHz on downlink), EU R & TTE frequencies (880-915 MHz on uplink and 925-960 MHz on downlink), EU R & TTE frequencies (1710-1785 MHz on uplink and 1805-1880 MHz on downlink), EU R & TTE frequencies (1920-1980 MHz on uplink and 2110-2170 MHz on downlink), US FCC frequencies (806-824 MHz on uplink and 851-869 MHz on downlink), US FCC frequencies (896-901 MHz on uplink and 929-941 MHz on downlink), US FCC frequencies (793-805 MHz on uplink and 763-775 MHz on downlink), and US FCC frequencies (2495-2690 MHz on uplink and downlink), and medical telemetry frequencies.

[0042] As discussed above with regard to distributed communication system 40 in FIG. 2 the ultrasound beacons 42(1)-42(B), 42(M) are synchronized. This is opposed to having to synchronize the client devices 48 to the ultrasound beacons 42(1)-42(B), 42(M). The ultrasound beacons 42(1)-42(B), 42(M) are synchronized to each other so that the ultrasound pulses 46, 46(M) are emitted by the ultrasound beacons 42(1)-42(B), 42(M) in synchronization to the client devices 48. In this manner, the client devices 48 can distinguish between ultrasound pulses 46, 46(M) received from different ultrasound beacons 42(1)-42(B), 42(M) to analyze their time-difference-of-arrivals to determine location. In this regard, FIG. 4 provides a flowchart illustrating an exemplary process of an ultrasound beacon 42(1)-42(B), 42(M) receiving RF synchronization signals 53 including synchronization information 51. The synchronization information 51 is used by the ultrasound beacons 42(1)-42(B), 42(M) to synchronize their internal clocks used to synchronize ultrasound pulse 46, 46(M) emission. Alternatively, the synchronization information 51 may be a central clock signal that is received by all ultrasound beacons 42(1)-42(B), 42(M) and used to synchronize ultrasound pulse 46, 46(M) emission.

[0043] With reference to FIG. 4, a controller 80 of the ultrasound beacon 42(1)-42(B),

42(M), which is schematically illustrated by example in **FIG. 5** determines if a RF synchronization signal **53** having encoded synchronization information **51** has been received (block **70** in **FIG. 4**). As illustrated in **FIG. 5**, the ultrasound beacon **42(1)-42(B)**, **42(M)** includes an RF antenna **82** coupled to a RF receiver **84**. The RF antenna **82** is configured to receive the RF synchronization signal **53** having the encoded synchronization information **51**. For example, the RF synchronization signal **53** may be communicated using a radio frequency identification (RFID), Zigbee, or Dash7 protocol, as non-limiting examples. The RF antenna **82** is coupled to the RF receiver **84**, which is configured to provide the encoded synchronization information **51** to the controller **80**. The controller **80** is coupled to memory **86** that includes instruction store **88** and data store **90**. The instruction store **88** contains instructions executed by the controller **80** to control the operations of the ultrasound beacon **42(1)-42(B)**, **42(M)**. The data store **90** allows the synchronization information **51** to be stored as well as other data, such as an identification indicia of the ultrasound beacon **42(1)-42(B)**, **42(M)**, as examples.

[0044] With continuing reference to **FIG. 4**, the controller **80** can filter the RF synchronization signal **53** for the encoded synchronization information **51** (block **72** in **FIG. 4**). The controller **80** can then use the synchronization information **51** to synchronize an internal clock **92** in the ultrasound beacon **42(1)-42(B)**, **42(M)**, as illustrated in **FIG. 5** (block **74** in **FIG. 4**). The internal clock **92** emits a clock signal **94** that is used by controller **80** to control the emission of ultrasound pulses **46**, **46(M)**. The controller **80** is coupled to an ultrasound emitter **96** that is configured to emit the ultrasound pulses **46**, **46(M)**. The ultrasound emitter **96** is coupled to at least one speaker **98** that emits the ultrasound pulses **46**, **46(M)** as sound that can be received and recorded by the client devices **48** to perform time-difference-of-arrival analysis to determine the location of the client device **48** in the distributed communication system **40**.

[0045] As one non-limiting synchronization example, the synchronization information **51** may be used by the ultrasound beacons **42(1)-42(B)**, **42(M)** to emit ultrasound pulses **46**, **46(M)** in sequence. The sequence of ultrasound pulses **46**, **46(M)** arriving at a client device **48** is the same as the emission sequence and temporal overlap of ultrasound pulses **46**, **46(M)** is avoided. In this manner, there is sufficient separation in the received ultrasound pulses **46**, **46(M)** for the client device **48** to be able to distinguish the receipt of the ultrasound pulses **46**, **46(M)** as being emitted from particular ultrasound beacons **42(1)-42(B)**, **42(M)**. The client device **48** can determine its location by subtracting timing offsets from the ultrasound pulse **46**, **46(M)** arrival times to determine the relevant propagation-induced time-difference-of-

arrival.

[0046] The ultrasound pulse **46, 46(M)** emission time offsets may be configured based on the synchronization information **51** to be larger than the maximum propagation time possible. The maximum propagation time possible depends on size in which an ultrasound beacon cluster **44(1)-44(A)** is disposed and the speed of sound at approximately 330 meters per second (m/s) (i.e., about 1 foot per millisecond (ms)). For example, the ultrasound beacons **42(1)-42(B), 42(M)** may be configured to emit ultrasound pulses **46, 46(M)** in approximately one millisecond (1 ms) durations to minimize or eliminate temporal overlap.

[0047] As another non-limiting synchronization example, the ultrasound pulses **46, 46(M)** could be emitted by different ultrasound beacons **42(1)-42(B), 42(M)** simultaneously or substantially simultaneously with the different ultrasound beacons **42(1)-42(B), 42(M)** emitting ultrasound pulses **46, 46(M)** at different carrier frequencies. Temporal overlap of received ultrasound pulses **46, 46(M)** by the client devices **48** can be tolerated since the ultrasound pulses **46, 46(M)** are separated in the frequency domain. The client devices **48** can distinguish which ultrasound beacons **42(1)-42(B), 44(M)** emitted which ultrasound pulses **46, 46(M)** in a spectral analysis of the received ultrasound pulses **46, 46(M)**.

[0048] As another non-limiting synchronization example, the ultrasound pulses **46, 46(M)** could be emitted by different ultrasound beacons **42(1)-42(B), 42(M)** and at different carrier frequencies. In this manner the sequence of ultrasound pulses **46, 46(M)** arriving at a client device **48** is the same as the emission sequence and temporal overlap of ultrasound pulses **46, 46(M)** is avoided. The client devices **48** can also distinguish which ultrasound beacons **42(1)-42(B), 42(M)** emitted which ultrasound pulses **46, 46(M)** in a spectral analysis of the received ultrasound pulses **46, 46(M)**. This example may be particular useful for larger rooms or areas requiring a larger number of ultrasound beacons **42(1)-42(B), 42(M)** to unambiguously associate ultrasound pulses **46, 46(M)** as being emitted by particular ultrasound beacons **42(1)-42(B), 42(M)**.

[0049] In this regard, **FIG. 6** is a flowchart illustrating an exemplary process of an ultrasound beacon **42(1)-42(B), 42(M)** emitting ultrasound pulses **46, 46(M)** to be received by the client devices **48** to determine their location. As discussed above, the master ultrasound beacon **42(M)** is configured to encode location information **50** of all the ultrasound beacons **42(1)-42(B), 42(M)** in ultrasound pulses **46(M)** emitted by the master ultrasound beacon **42(M)** to the client devices **48**. For example, the location information **50** could be enclosed in a coding scheme, such as frequency-shift-keying (FSK) for example, or other coding schemes, using the ultrasound pulses **46(M)** as an over-the-air interface. Thus,

if the ultrasound beacon **42(1)-42(B)**, **42(M)** is a master ultrasound beacon **42(M)** (block **100** in **FIG. 6**), the master ultrasound beacon **42(M)** determines if it is time to encode the location information **50** in ultrasound pulses **46(M)** to be emitted to the client devices **48** (block **102** in **FIG. 6**). It may only be desired to periodically, and less often than normal emission of ultrasound pulses **46(M)** for time-difference-of-arrival analysis, emit ultrasound pulses **46(M)** encoded with the location information **50** to the client devices **48**. Alternatively, periodically in this context could mean as often as the ultrasound pulses **46(M)** are emitted by the master ultrasound beacon **42(M)** for time-difference-of-arrival analysis.

[0050] With continuing reference to **FIG. 6**, if it is time to encode the location information **50** in ultrasound pulses **46(M)** to be emitted to the client devices **48** (block **102** in **FIG. 6**), the controller **80** of the master ultrasound beacon **42(M)** causes the ultrasound emitter **96** in **FIG. 5** to emit ultrasound pulses **46(M)** with encoded location information **50** of the location of the ultrasound beacons **42(1)-42(B)**, **42(M)** in the ultrasound beacon cluster **44** to the client devices **48** (block **104** in **FIG. 6**). Thereafter, regardless of whether the ultrasound beacon **42** is a master ultrasound beacon **42(M)** or a non-master ultrasound beacon **42(1)-42(B)**, the controller **80** of the ultrasound beacon **42(1)-42(B)**, **42(M)** controls emission of the ultrasound pulses **46(M)** to be in synchronization with other ultrasound beacons **42(1)-42(B)**, **42(M)** to the client devices **48** (block **106** in **FIG. 6**). The synchronization methods employed by the controller **80** can include any of the synchronization techniques previously described above to allow the client devices **48** to distinguish between which particular ultrasound beacons **42(1)-42(B)**, **42(M)** the received ultrasound pulses **46**, **46(M)** were emitted. The controller **80** may delay the emission of the next ultrasound pulses **46**, **46(M)** by the ultrasound emitter **96** next depending on the synchronization method employed (block **108** in **FIG. 6**).

[0051] **FIGS. 7A** and **7B** are flowcharts illustrating an exemplary process of the client device **48** receiving ultrasound pulses **46**, **46(M)** from ultrasound beacons **42(1)-42(B)**, **42(M)** and using the time-difference-of-arrival of the received ultrasound pulses **46**, **46(M)** to determine location. **FIG. 8** is a schematic diagram of an exemplary client device **48** discussed in conjunction with **FIGS. 7A** and **7B**. With reference to **FIG. 7A**, a controller **150** of the client device **48** (**FIG. 8**) determines if it is time to record sound received by a microphone **152** coupled to an ultrasound receiver **154** to receive ultrasound pulses **46**, **46(M)** (block **110** in **FIG. 7A**). It may be desired for the controller **150** of the client device **48** to only determine location at particular times to conserve power or processing capability of the controller **150**. It may also be desired of the controller **150** of the client device **48** to only

record sound to receive ultrasound pulses **46, 46(M)** when directed by a user through input **158** on a user interface **156** provided in the client device **48**.

[0052] With continuing reference to **FIG. 7A**, if it is not time to record sound to receive ultrasound pulses **46, 46(M)**, the controller **150** continues to make this determination (block **110** in **FIG. 7A**) until it is time to record sound received by a microphone **152** coupled to an ultrasound receiver **154**. When it is time to record sound, the controller **150** directs the ultrasound receiver **154** to receive sound received by the microphone **152** and record the sound in memory **160** for a defined period of time (block **112** in **FIG. 7A**). The memory **160** also contains the instructions that are executed by the controller **150** to perform the location determination operations discussed herein in this example. For example, these instructions may be provide in a location applet **162** stored in memory **160**.

[0053] With continuing reference to **FIG. 7A**, the ultrasound pulses **46, 46(M)** are communicated by the ultrasound beacons **42(1)-42(B), 42(M)** at one or more carrier frequencies. As discussed above, the ultrasound beacons **42(1)-42(B), 42(M)** may be configured to emit ultrasound pulses **46, 46(M)** on the same carrier frequency or different, unique carrier frequencies depending on whether ultrasound pulses **46, 46(M)** are emitted in sequence synchronization or in simultaneous emission synchronization. Thus, the controller **150** is configured in this example to convert the recorded sound into a frequency domain by performing a Fourier transform on the recorded sound to produce a spectrum of the recorded sound (block **114** in **FIG. 7A**). The controller **150** may then be configured to filter the spectrum of recorded sound for the expected ultrasound beacon **42(1)-42(B), 42(M)** carrier frequency(ies) to recover the location information **50** of the ultrasound beacons **42(1)-42(B), 42(M)** and the ultrasound pulse **46, 46(M)** arrival times (block **116** in **FIG. 7A**). Out-of-band frequencies may be filtered out of the recorded sound since the microphone **152** will pick up other surrounding environmental noise, including ambient noise in the recorded sound (block **116** in **FIG. 7A**).

[0054] With continuing reference to **FIG. 7A**, the controller **150** of the client device **48** may then transform the spectrum of recorded sound back into the time domain via a reverse Fourier transform so that the recorded sound can be analyzed in the time domain for time difference-of-arrival (block **118** in **FIG. 7A**). In this regard, the client device **48** can perform the exemplary process in **FIG. 7B** to process the filtered recorded sound to determine if location information **50** for the ultrasound beacons **42(1)-42(B), 42(M)** is present in the filtered recorded sound. This processing example is shown assuming the location information **50** is encoded in the ultrasound pulses **46, 46(M)** using FSK (Frequency Shift

Key) encoding, but other encoding schemes could be employed, such as ASK (Amplitude Shift Keying), PSK (Phase Shift Keying), or other encoding schemes as non-limiting examples.

[0055] In this regard, as a non-limiting example, the client device **48** checks to see if the filtered, recorded sound transmission contains ultrasound pulses or data at the expected carrier frequency(ies) of the ultrasound beacons **42(1)-42(B)**, **42(M)** (block **120** in **FIG. 7B**). If not, an ultrasound beacon data valid flag can be cleared in memory **160** of the client device **48** indicating that data expected to contain location information **50** is not present in the filtered recorded sound (block **122** in **FIG. 7B**). The process continues to check to see if the filtered recording sound transmission contains data expected to contain location information **50** (block **120** in **FIG. 7B**). When data is detected in the filtered recorded sound (block **120** in **FIG. 7B**), the client device **48** checks to see if the ultrasound beacon **42(1)-42(B)**, **42(M)** locations are already known from prior received filtered recorded sound from the ultrasound beacon **42(1)-42(B)**, **42(M)** by checking the ultrasound beacon data valid flag in memory **160** (block **124** in **FIG. 7B**). If set, the process returns to block **138** in **FIG. 7A** to continue with time-difference-of-arrival analysis, since location information **50** has been previously received and stored in memory **160** for use in time-difference-of-arrival analysis. If not set, the filtered recording sound is analyzed to recover the location information **50** for use by the client device **48** to perform time-difference-of-arrival analysis using a software zero crossing detector in this example, which outputs an array in memory **160** that indicates the pulse width of signal above zero and below zero (block **126** in **FIG. 7B**).

[0056] In this regard, with continuing reference to **FIG. 7B**, this array indicative of pulse width of signal above zero and below zero can then be passed to a routine, that measures the pulse widths and builds a binary array that indicates if the ultrasound waveform period was representative of a one or zero when encoded (block **128** in **FIG. 7B**). This array is then passed to a routine that looks for a preamble (indicated by a stream of ones longer than a single transmitted byte) (block **130** in **FIG. 7B**). The binary data present after the preamble is the desired data, which is a series of ones and zeros in which there are two (2) entries for one (1) cycle of the encoded frequency burst in this example (block **132** in **FIG. 7B**). The widths of the binary data are measured, and the original encoded binary data is reconstituted (block **134** in **FIG. 7B**). This binary data has all framing bits removed, and is converted to ASCII (block **134** in **FIG. 7B**). The ultrasound beacon **42(1)-42(B)**, **42(M)** locations are determined from the data received, either directly (i.e. GPS coordinates were sent) or indirectly (i.e. a database key was sent, a lookup performed, and the coordinates are

populated as the location information **50**, as non-limiting examples (block **136** in **FIG. 7B**).

[0057] With reference back to **FIG. 7A**, with location information **50** obtained from ultrasound beacons **42(1)-42(B)**, **42(M)**, the controller **150** can then perform a time-difference-of-arrival analysis of the received ultrasound pulses **46**, **46(M)** from the filtered recorded sound in the time domain (block **138** in **FIG. 7A**). The controller **150** can determine its distance from the ultrasound beacons **42(1)-42(B)**, **42(M)** in which ultrasound pulses **46**, **46(M)** are received based on associating the time-difference in the arrival of the ultrasound pulses **46**, **46(M)** with particular pairs of ultrasound beacons **42(1)-42(B)**, **42(M)**. Examples of time-difference-of-arrival analysis can be found in K.C. Ho and Y.T. Chan, IEEE Transactions on Aerospace and Electronic Systems, Vol. 29, No. 4, October 1993, pp. 1311-1322, which is incorporated herein by reference in its entirety. This time-difference-of-arrival analysis provides the relative distance of the client device **48** from the ultrasound beacons **42(1)-42(B)**, **42(M)** in which ultrasound pulses **46**, **46(M)** are received. The controller **150** of the client device **48** can then perform position multi-lateration calculations using the time-difference-of-arrival information from the received ultrasound pulses **46**, **46(M)** and the location information **50** of the ultrasound beacons **42(1)-42(B)**, **42(M)** to determine the relative location of the client device **48** to the ultrasound beacons **42(1)-42(B)**, **42(M)** (block **140** in **FIG. 7A**). This relative location can be determined if ultrasound pulses **46**, **46(M)** from at least two (2) ultrasound beacons **42(1)-42(B)**, **42(M)** are received by the client device **48**. This relative location may be only relative to the location information **50** of the ultrasound beacons **42(1)-42(B)**, **42(M)** provided to the client device **48**. Location information **50** from two ultrasound beacons **42(1)-42(B)**, **42(M)** can allow the client device **48** to determine a boundary of possible locations of the client device **48**. Location information **50** from three (3) or more ultrasound beacons **42(1)-42(B)**, **42(M)** can allow the client device **48** to determine exact locations relative to the two ultrasound beacons **42(1)-42(B)**, **42(M)**. As a non-limiting example, this relative location can be an absolute (i.e., non-relative) location (e.g., coordinates, also e.g., X, Y, and/or Z (i.e., longitude, latitude, and/or altitude) coordinates) if the location information **50** of the ultrasound beacons **42(1)-42(B)**, **42(M)** provided to the client device **48** are absolute locations.

[0058] With continuing reference to **FIG. 7A**, the client device **48** can store its determined location in memory **160** and/or communicate this determined location to another device or network (block **142** in **FIG. 7A**). For example, as illustrated in **FIG. 8**, the client device **48** may include a RF transceiver **164** coupled to the controller **150** to process RF communication. The RF transceiver **164** is coupled to a RF antenna **166** for RF wireless

transmissions and receptions. As a non-limiting example, the client device **48** could transmit the determined location wirelessly in a RF communication through the RF transceiver **164** and RF antenna **166** to another device or network. For example, the client device **48** could wirelessly transmit the determined location to a remote unit **66(1)-66(N)** in the distributed communication system **40** in **FIG. 2**. Thus, the client device **48** could use the distributed communication system **40** to also distribute its determined location. The identification of the client device **48** may also be included in this RF communication. The remote unit **66(1)-66(N)** could distribute this determined location of the client device **48** as an uplink communication signal **56U** to the central unit **62**. The determined location of the client device **48** could be stored in memory **150** of the central unit **62**, as illustrated in **FIG. 9**. The determined location of the client device **48** could also be communicated by the central unit **62** to a base station **58** and/or the network **60**. The process can repeat by returning back to block **110** in **FIG. 7A** until the next recording is triggered by the controller **150**.

[0059] As discussed above and illustrated in **FIG. 2**, the ultrasound beacons **42(1)-42(B)**, **42(M)** are provided in the distributed communication system **40** apart from other components in the distributed communication system **40**. However, the ultrasound beacons **42(1)-42(B)**, **42(M)** could be co-located and/or included in the other components and/or their housings in the distributed communication system **40**. For example, as illustrated in **FIG. 9**, the ultrasound beacons **42(1)-42(B)**, **42(M)** are shown as being co-located and included in the remote units **66(1)-66(N)**. In this manner, if the determined locations of the client devices **48** are provided to the remote unit **66(1)-66(N)**, wireless RF communication through the RF antenna **68** coupled to a RF interface **152(1)-152(N)** in the remote units **66(1)-66(N)** to do so would not be necessary. The ultrasound beacons **42(1)-42(B)**, **42(M)** could provide the determined location information of the client devices **48** to the remote unit **66(1)-66(N)** over wired connections/interfaces. Further, in this arrangement, if the synchronization information **51** is provided through the remote units **66(1)-66(N)** to the ultrasound beacons **42(1)-42(B)**, **42(M)**, RF communication would not be necessary to provide the synchronization information **51** to the ultrasound beacons **42(1)-42(B)**, **42(M)**. The synchronization information **51** could be provided through wired connections/interfaces from the remote units **66(1)-66(N)** to the ultrasound beacons **42(1)-42(B)**, **42(M)**.

[0060] In an exemplary embodiment, better illustrated in **FIG. 10** an ultrasound cluster **44'** includes only two ultrasound beacons **42(1)** & **42(2)**. This embodiment is particularly well suited for use in hallways within a building. The received information **51** may include the reference clock signal and the ultrasound signals **46(1)** and **46(2)** are used by the client

device 48 to calculate a first position as previously described. While this embodiment is well suited for use in corridors of buildings, ultrasound pulses are not likely to penetrate walls and enter rooms to either side of the corridor. Thus, the client device 48 needs some alternate method through which it may continue to calculate a current position.

[0061] In one embodiment, the alternate method is through the use of an inertial navigation system (INS) such as INS 200 of the client device 48 illustrated in FIG. 8. In an exemplary embodiment, the INS 200 includes an accelerometer 202, a gyroscope 204 and a compass 206. Many conventional smart phones include these elements and/or comparable INS elements. Additionally, while only one accelerometer 202 and one gyroscope 204 are illustrated, it should be appreciated that in some embodiments, a plurality of such devices may be present with orthogonal axes. Thus, in an exemplary embodiment, there may be three accelerometers 202 and three gyroscopes 204.

[0062] An exemplary methodology 210 for using the INS 200 is provided with reference to FIG. 11. The client device 48 initially determines or calculates its position using signals received from the ultrasound beacons 42(1) and 42(2) (block 212). The position calculated from the ultrasound signals may be considered a first position. The client device 48 may move within the building and will monitor to see if the received ultrasound signals exceed a predetermined threshold (block 214). The predetermined threshold corresponds to a signal strength sufficient from which to extract meaningful data. If the answer to block 214 is yes, the signal strength remains above the threshold, and then the client device 48 calculates its position using the received ultrasounds signals from the ultrasound beacons 42. If the client device 48 moves enough, it may be passed to a different ultrasound cluster 44 or different ultrasound beacons 42.

[0063] If the answer to block 214 is no, the ultrasound signal strength has fallen below a predefined threshold, then the client device 48 begins using the INS 200 to calculate a second position (block 216) using the first position from the ultrasound beacons 42 as a starting point. Use of an INS 200 is well understood as evidenced by the work of D.H. Titterton and J. Weston in Strapdown Inertial Navigation Technology, published by American Institute of Aeronautics and Astronautics, Second Edition, 2004. If at a subsequent time, the client device 48 begins receiving ultrasound signals above the predefined threshold, then the client device may return to block 212 and calculate a current position using the ultrasound signals. Otherwise, the client device 48 continues to use the INS 200 to determine its current position.

[0064] In an alternate embodiment, the ultrasound techniques of the present disclosure are used to assist other location based services (LBS) and systems supporting such LBS to

pinpoint a location of a client device. That is, there are times when an LBS may not be able to pinpoint a location of a client device with sufficiently fine resolution. Thus, an ultrasound system may be concurrently deployed to supplement the location determination. In this regard, **FIGS. 12** and **13** respectively illustrate a schematic diagram and a flow chart of such ultrasound assistance in a location determination system **250**. The location determination system **250** may include a central unit **62** with a distributed communication system formed by remote units **66**, which may include WLAN communication elements including location based services systems for WLAN systems such as those used in infrared, ZIGBEE, BLUETOOTH, cellular location elements, or comparable systems. In addition to the remote units **66**, the distributed communication system may include ultrasound beacons **42(1)-42(N)**. The ultrasound beacons **42** may be in direct communication with the location determination system **250** (illustrated) or a separate system (not illustrated) as desired. It should be appreciated that the structure of the building in which the location determination system **250** is installed may create spots where the location determination elements of the WLAN components are inadequate to ascertain a location of a client device with sufficient particularity. In this regard, the ultrasound elements may be used to provide supplementary location information and the client device may use whichever system provides a better location resolution as desired and as further explicated with reference to **FIG. 13**.

[0065] In this regard, **FIG. 13** provides a flow chart **300**, which begins by ascertaining whether the signal strength of the ultrasound signals from the ultrasound beacons **42** is above a predefined threshold (block **302**). If the answer is yes, the signal strength of the ultrasound signals is above the predefined threshold, and then the client device **48** may calculate its position using the ultrasound beacons (block **304**). Additionally, the client device **48** reports its current position to the central unit **62** through the remote units **66** as appropriate and/or as available.

[0066] With continuing reference to **FIG. 13**, if the answer to block **302** is no, the signal strength of the ultrasound signals is not above the predefined threshold, then the client device **48** may calculate its position using the signals from the WLAN elements such as remote units **66** (block **306**). The client device **48** may monitor both the signals from the remote units **66** and the ultrasound beacons **42** to ascertain whether a position can be refined using the ultrasound signals (block **308**). If the position can be refined, then the position is refined using the ultrasound signals (block **310**). Again, this refined position may be reported to the system through the remote units **66** as desired. If the position cannot be refined, the process repeats as indicated. In essence, the embodiment of **FIGS. 12** and **13** uses the better of the

two location systems to assist the client device 48 to get the best location it can. This best location information may be provided back to the location system as desired. By way of analogy, the ultrasound system may replace checkpoint based RFID systems that are sometimes installed when room level accuracy is required.

[0067] As discussed above, the ultrasound beacons 42(1)-42(B), 42(M) and client devices 48 execute instructions from a computer-readable medium (i.e., instructions in memory). The term “computer-readable medium” should be taken to include a single medium or multiple media (e.g., a centralized or distributed database, and/or associated caches and servers) that store the one or more sets of instructions. The term “computer-readable medium” shall also be taken to include any medium that is capable of storing, encoding or carrying a set of instructions for execution by the processing device and that cause the processing device to perform any one or more of the methodologies of the embodiments disclosed herein. The term “computer-readable medium” shall accordingly include solid-state memories, optical and magnetic medium, and carrier wave signals.

[0068] The embodiments disclosed herein include various steps. The steps of the embodiments disclosed herein may be performed by hardware components or may be embodied in machine-executable instructions, which may be used to cause a general-purpose or special-purpose processor programmed with the instructions to perform the steps. Alternatively, the steps may be performed by a combination of hardware and software.

[0069] The embodiments disclosed herein may be provided as a computer program product, or software, that may include a machine-readable medium (or computer-readable medium) having stored thereon instructions, which may be used to program a computer system (or other electronic devices) to perform a process according to the embodiments disclosed herein. A machine-readable medium includes any mechanism for storing or transmitting information in a form readable by a machine (e.g., a computer). For example, a machine-readable medium includes a machine-readable storage medium (e.g., read only memory (“ROM”), random access memory (“RAM”), magnetic disk storage medium, optical storage medium, flash memory devices, etc.), a machine-readable transmission medium (electrical, optical, acoustical or other form of propagated signals (e.g., carrier waves, infrared signals, digital signals, etc.)), etc.

[0070] Unless specifically stated otherwise, discussions utilizing terms such as “processing,” “computing,” “determining,” “displaying,” or the like, refer to processes of a computer system, or similar electronic computing device, that manipulates and transforms data represented as physical (electronic) quantities within the computer system’s registers and

memories into other data similarly represented as physical quantities within the computer system memories or registers or other such information storage, transmission, or display devices.

[0071] The algorithms and displays presented herein are not inherently related to any particular computer or other apparatus. Various systems may be used with programs in accordance with the teachings herein, or it may prove convenient to construct more specialized apparatuses to perform the required method steps. The required structure for a variety of these systems will appear from the description above. A variety of programming languages may be used to implement the teachings of the embodiments as described herein.

[0072] The various illustrative logical blocks, modules, circuits, and algorithms described in connection with the embodiments disclosed herein may be implemented as electronic hardware, instructions stored in memory or in another computer-readable medium and executed by a processor or other processing device, or combinations of both. The components of the distributed antenna systems described herein may be employed in any circuit, hardware component, integrated circuit (IC), or IC chip, as examples. Memory disclosed herein may be any type and size of memory and may be configured to store any type of information desired. To clearly illustrate this interchangeability, various illustrative components, blocks, modules, circuits, and steps are described generally in terms of their functionality.

[0073] The logical blocks, modules, and circuits described in connection with the embodiments disclosed herein may be implemented with a processor, a Digital Signal Processor (DSP), an Application Specific Integrated Circuit (ASIC), a Field Programmable Gate Array (FPGA) or other programmable logic device, discrete gate or transistor logic, discrete hardware components, or any combination thereof designed to perform the functions described herein. A controller may be a processor, which may be a microprocessor or any conventional processor, controller, microcontroller, or state machine. A processor may also be implemented as a combination of computing devices, e.g., a combination of a DSP and a microprocessor, a plurality of microprocessors, one or more microprocessors in conjunction with a DSP core, or any other such configuration.

[0074] The embodiments disclosed herein may be embodied in hardware and in instructions that are stored in hardware, and may reside, for example, in Random Access Memory (RAM), flash memory, Read Only Memory (ROM), Electrically Programmable ROM (EPROM), Electrically Erasable Programmable ROM (EEPROM), registers, a hard disk, a removable disk, a CD-ROM, or any other known form of computer-readable medium.

An exemplary storage medium is coupled to the processor such that the processor can read information from, and write information to, the storage medium. Alternatively, the storage medium may be integral to the processor. The processor and the storage medium may reside in an ASIC, which may reside in a remote station. Alternatively, the processor and the storage medium may reside as discrete components in a remote station, base station, or server.

[0075] The operational steps described in any of the embodiments herein are described to provide examples and discussion, and may be performed in different sequences other than the illustrated sequences. Operations described in a single step may actually be performed in a number of different steps, and one or more operational steps may be combined. Data, instructions, commands, information, bits, symbols, and chips that may be referenced throughout the above description may be represented by voltages, currents, electromagnetic waves, magnetic fields or particles, optical fields or particles, or any combination thereof.

[0076] Further, as used herein, it is intended that terms “fiber optic cables” and/or “optical fibers” include all types of single mode and multi-mode light waveguides, including one or more optical fibers that may be upcoated, colored, buffered, ribbonized and/or have other organizing or protective structure in a cable such as one or more tubes, strength members, jackets or the like.

[0077] The antenna arrangements may include any type of antenna desired, including but not limited to dipole, monopole, and slot antennas. The distributed antenna systems disclosed herein could include any type or number of communication mediums, including but not limited to electrical conductors, optical fiber, and air (i.e., wireless transmission). The systems may distribute and the antenna arrangements disclosed herein may be configured to transmit and receive any type of communication signals, including but not limited to RF communication signals and digital data communication signals, examples of which are described in U.S. Patent Application No. 12/892,424, incorporated herein by reference. Multiplexing, such as WDM and/or FDM, may be employed in any of the distributed antenna systems described herein, such as according to the examples described in U.S. Patent Application No. 12/892,424.

[0078] Various modifications and variations can be made without departing from the scope of the present disclosure. Since modifications combinations, sub-combinations and variations of the disclosed embodiments incorporating the spirit and substance of the present disclosure may occur to persons skilled in the art, the present disclosure should be construed to include everything within the scope of the appended claims and their equivalents.

What is claimed is:

1. A client device configured to communicate in a distributed communication system, comprising:
 - a controller;
 - an ultrasound receiver coupled to the controller, the ultrasound receiver configured to receive ultrasound pulses over at least one microphone; and
 - a radio-frequency (RF) transceiver coupled to the controller, the RF transceiver configured to wirelessly receive and transmit RF communication signals over at least one antenna;
 - an inertial navigation system (INS) operatively coupled to the controller;
 - the controller configured to:
 - calculate a position using received ultrasound signals; and
 - use the INS to calculate a second position from the first position when the received ultrasound signals are below a predefined threshold.

2. The client device of claim 1, wherein the controller is configured to calculate the position using received ultrasound signals by being configured to:
 - record sound received from a plurality of ultrasound beacons over the at least one microphone over a defined period of time;
 - filter the recorded sound about at least one ultrasound beacon frequency;
 - recover a plurality of ultrasound pulses from the filtered recorded sound emitted from a plurality of ultrasound beacons in the distributed communication system;
 - perform a time-difference-of-arrival analysis on the recovered plurality of ultrasound pulses; and
 - determine a relative distance of the client device to the plurality of ultrasound beacons.

3. The client device of claim 1, wherein the controller is further configured to transform the recorded sound in a frequency domain to produce a spectrum of the recorded sound.

4. The client device of claim 3, wherein the controller is configured to filter the recorded sound by filtering the spectrum of the recorded sound about the at least one ultrasound beacon frequency.

5. The client device of claim 3, wherein the controller is further configured to transform filtered spectrum of recorded sound back to a time domain.
6. The client device of any of claims 1 to 5, wherein the INS comprises:
 - at least one accelerometer;
 - a compass; and
 - at least one gyroscope.
7. The client device of any of claims 1 to 6, wherein the controller is configured to calculate a third position if the received ultrasound signals are subsequently above the threshold.
8. The client device of any of claims 1 to 7, wherein the received ultrasound signals are received from a distributed antenna system.
9. The client device of any of claims 1 to 8, wherein the received ultrasound signals are received staggered in time.
10. The client device of claim 2, wherein the controller is further configured to store the relative distance of the client device to the plurality of ultrasound beacons in memory.
11. The client device of claim 2, wherein the controller is further configured to:
 - recover location information of a master ultrasound beacon in the distributed communication system from the filtered recorded sound from a plurality of ultrasound beacons in the distributed communication system; and
 - determine the relative location of the client device to the master ultrasound beacon based on applying the location information to the relative distance.
12. The client device of claim 11, wherein the controller is configured to determine the relative location of the client device to the master ultrasound beacon based on performing position multi-lateration calculations using the determined time-difference-of-arrival of the recovered plurality of ultrasound pulses and the relative location of the client device to the master ultrasound beacon.

13. The client device of claim 11, wherein the controller is further configured to communicate the relative location of the client device to another device or network.
14. The client device of any of claims 2 to 13, wherein the controller is configured to communicate the relative location of the client device to a remote unit in the distributed communication system.
15. A method of a RF communication client device configured to communicate in a distributed communication system for determining location within the distributed communication system, comprising:
 - calculating a first position using ultrasound signals received at the client device; and
 - calculating a second position using an inertial navigation system within the client device when a signal strength of the ultrasound signals falls below a predefined threshold.
16. The method of claim 15, wherein calculating the first position comprises:
 - recording sound received from a plurality of ultrasound beacons over at least one microphone over a defined period of time;
 - filtering the recorded sound about at least one ultrasound beacon frequency;
 - recovering a plurality of ultrasound pulses from the filtered recorded sound emitted from a plurality of ultrasound beacons in the distributed communication system;
 - performing a time-difference-of-arrival analysis on the recovered plurality of ultrasound pulses; and
 - determining a relative distance of the RF communication client device to the plurality of ultrasound beacons.
17. The method of either of claims 15 or 16, further comprising transforming to the recorded sound in a frequency domain to produce a spectrum of the recorded sound.
18. The method of claim 17, comprising filtering the recorded sound by filtering the spectrum of the recorded sound about the at least one ultrasound beacon frequency.
19. The method of claim 17, further comprising transforming the filtered spectrum of

recorded sound back to a time domain.

20. The method of any of claims 15 to 19, wherein calculating the second position comprises using at least one of an accelerometer, a compass, and a gyroscope.

21. The method of any of claims 15 to 20, further comprising calculating a third position if the received ultrasound signals are subsequently above the threshold.

22. The method of any of claims 15 to 21, further comprising receiving the ultrasound signals from a distributed antenna system.

23. The method of any of claims 15 to 22, further comprising receiving the ultrasound signals staggered in time.

24. The method of claim 16, further comprising:
recovering location information of a master ultrasound beacon in the distributed communication system from the filtered recorded sound from a plurality of ultrasound beacons in the distributed communication system; and
determining a relative location of the RF communication client device to the master ultrasound beacon based on applying the location information to the relative distance.

25. The method of claim 24, further comprising determining the relative location of the RF communication client device to the master ultrasound beacon based on performing position multi-lateration calculations using the determined time-difference-of-arrival of the recovered plurality of ultrasound pulses and the relative location of the client device to the master ultrasound beacon.

26. The method of any of claims 24 to 25, further comprising communicating the relative location of the client device to another device or network.

27. The method of any of claims 24 to 26, comprising communicating the relative location of the client device to a remote unit in the distributed communication system.

28. A client device configured to communicate in a distributed communication system, comprising:
- a controller;
 - an ultrasound receiver coupled to the controller, the ultrasound receiver configured to receive ultrasound pulses over at least one microphone; and
 - a radio-frequency (RF) transceiver coupled to the controller, the RF transceiver configured to wirelessly receive and transmit RF communication signals over at least one antenna;
- the controller configured to:
- calculate a position using received ultrasound signals; and
 - use at least a portion of received RF communication signals to ascertain a second position of the client device.
29. The client device of claim 28, wherein the controller configured to ascertain the second position of the client device is configured to calculate the second position based on information received from a distributed communication system.
30. The client device of claim 28, wherein the controller configured to ascertain the second position is configured to receive the second location in information within the RF communication signals.
31. The client device of any of claims 28 to 30, wherein the controller is further configured to use the ultrasound receiver if a signal strength of the ultrasound pulses exceeds a predefined threshold.
32. The client device of any of claims 28 to 31, wherein the controller is further configured to use the portion of received RF communication signals if a signal strength of the ultrasound pulses does not exceed a predefined threshold.
33. The client device of any of claims 28 to 32, wherein the controller is further configured to inform a distributed communication system of the position calculated using the received ultrasound signals.
34. The client device of any of claims 28 to 33, wherein the received RF communication

signals are selected from the group consisting of: infrared signals, BLUETOOTH signals, and ZIGBEE signals.

35. A method of a RF communication client device configured to communicate in a distributed communication system for determining location within the distributed communication system, comprising:

calculating a first position using ultrasound signals received at the RF communication client device; and

determining a second position using location information received from the distributed communication system.

36. The method of claim 35, wherein determining the second position comprises calculating the second position within the RF communication client device.

37. The method of claim 35, wherein determining the second position comprises receiving the second position from the distributed communication system.

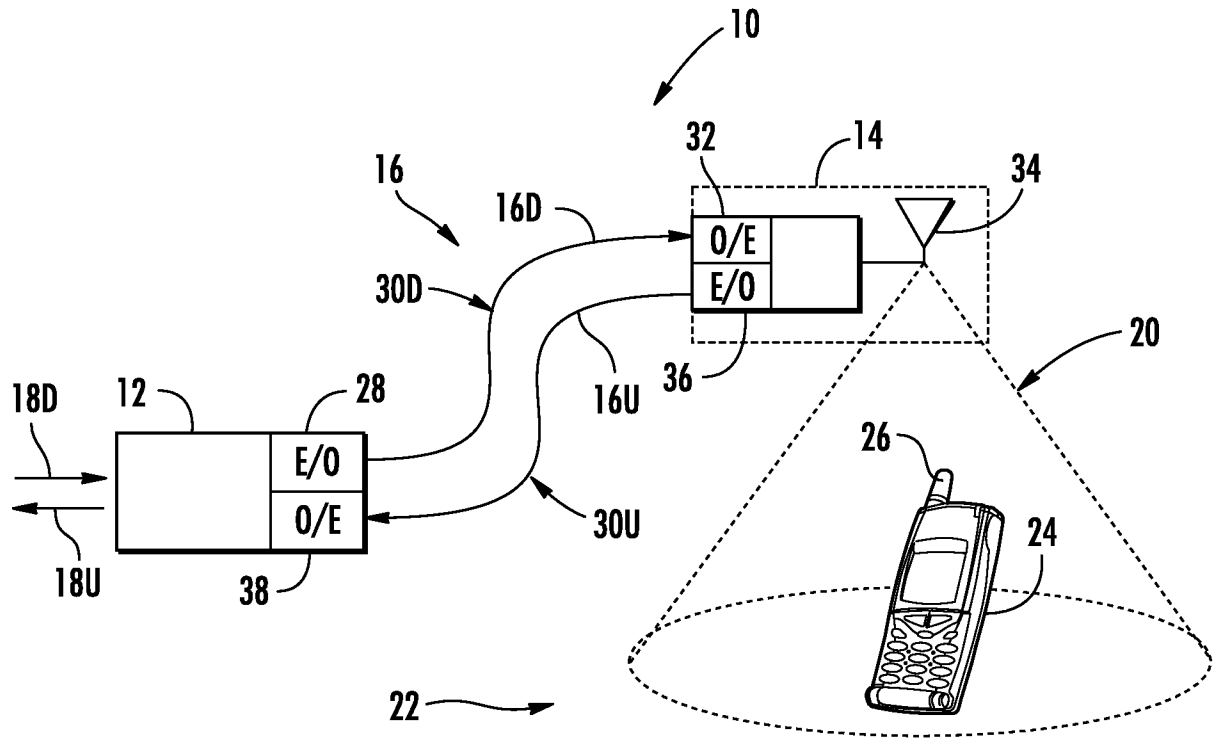


FIG. 1

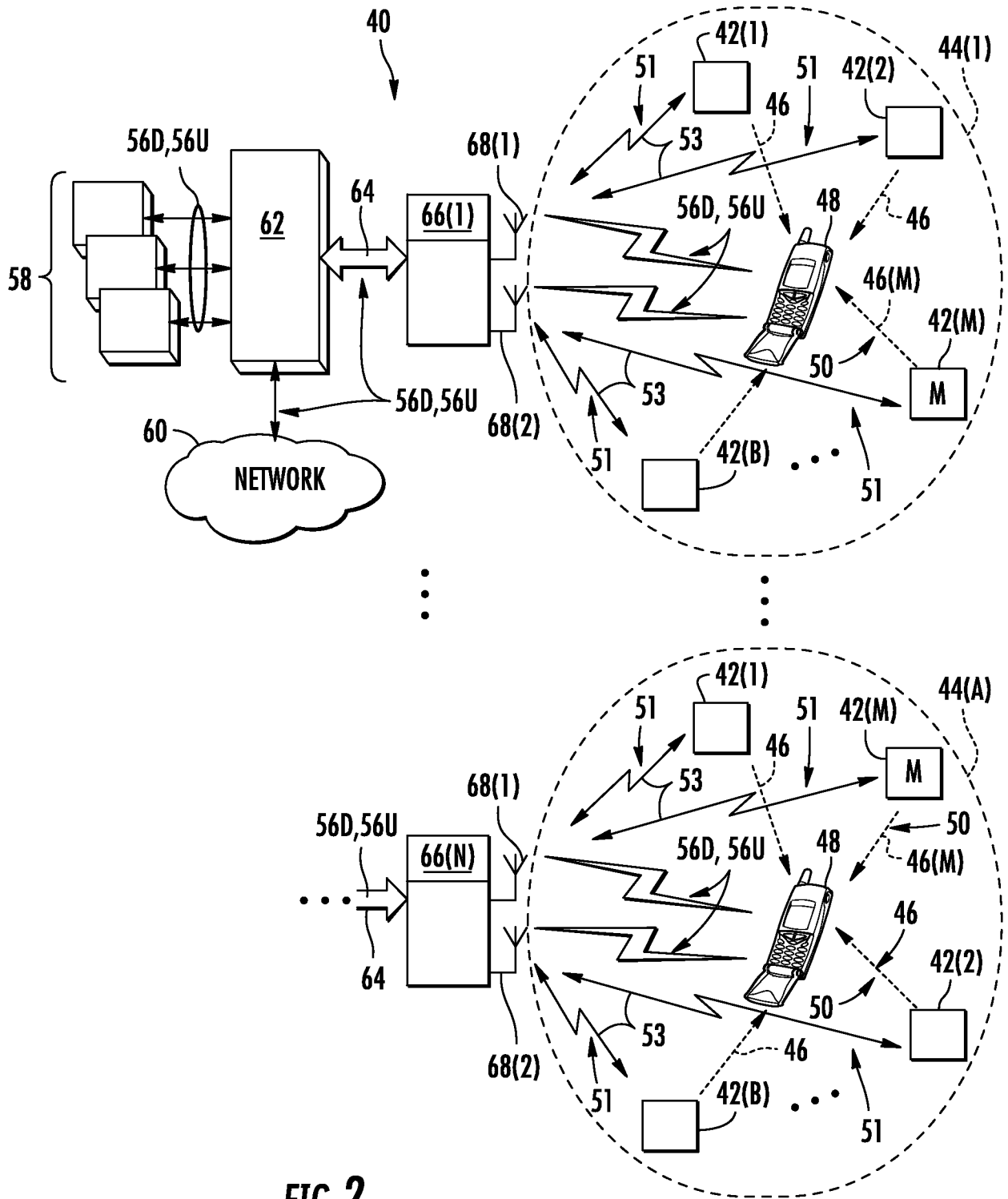


FIG. 2

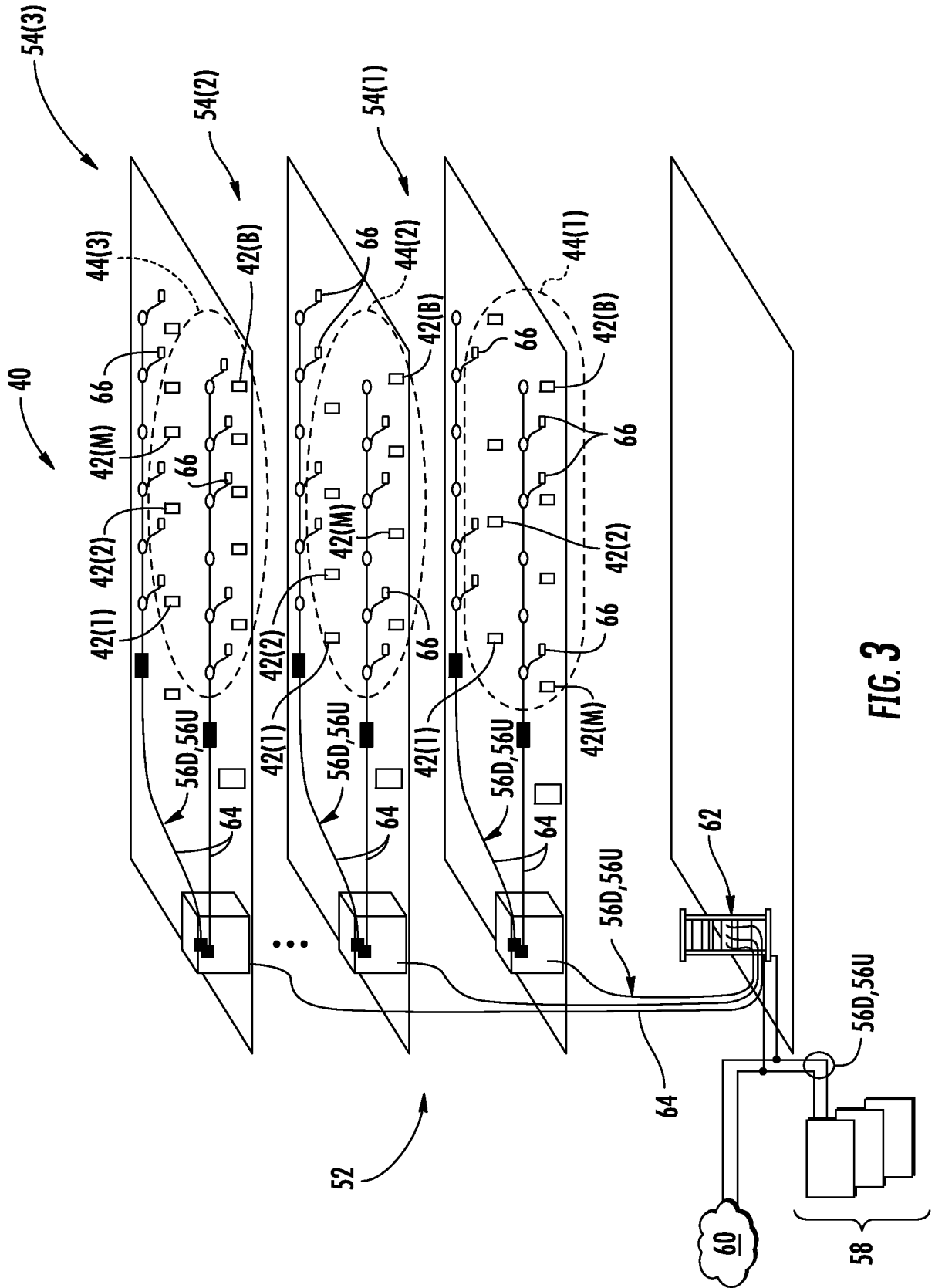


FIG. 3

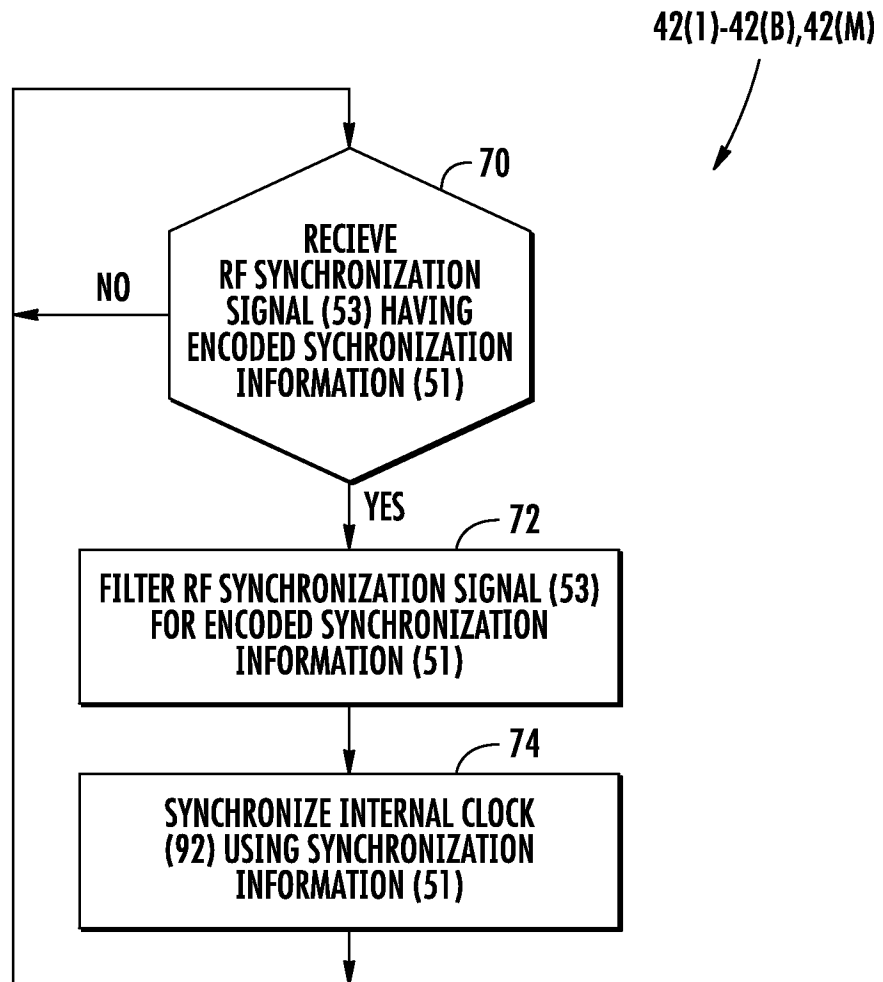


FIG. 4

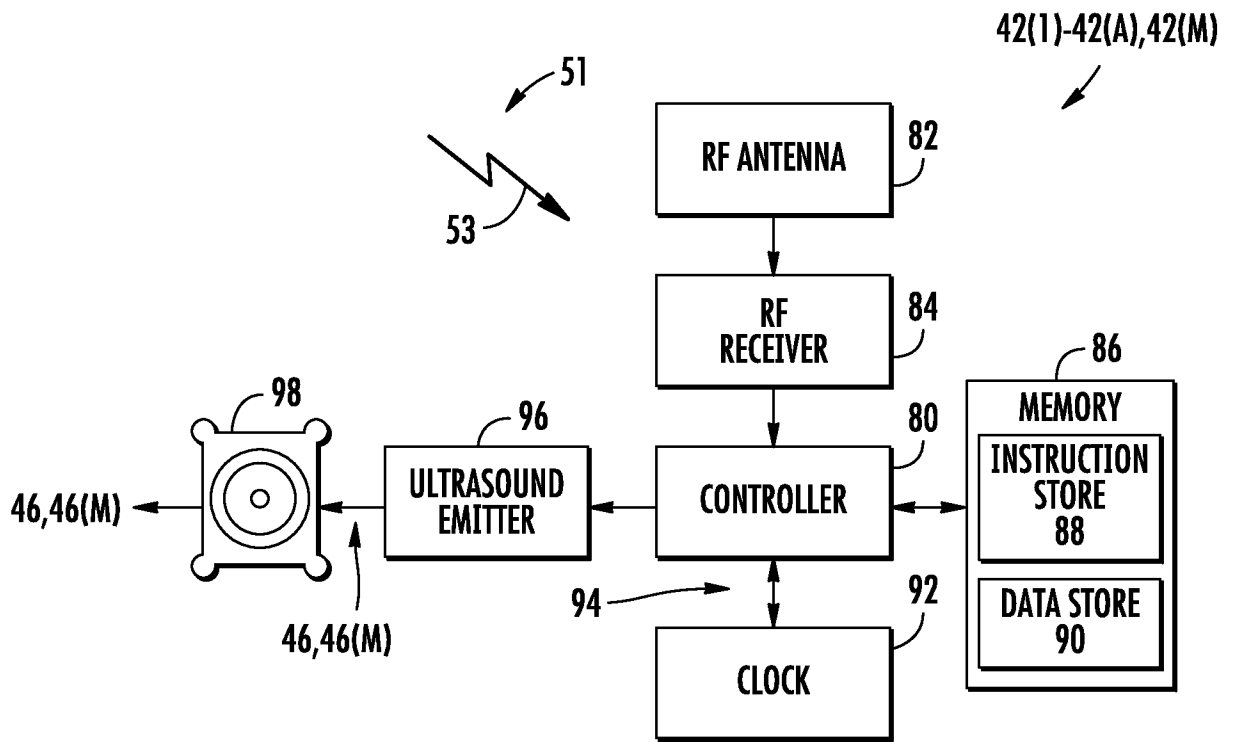


FIG. 5

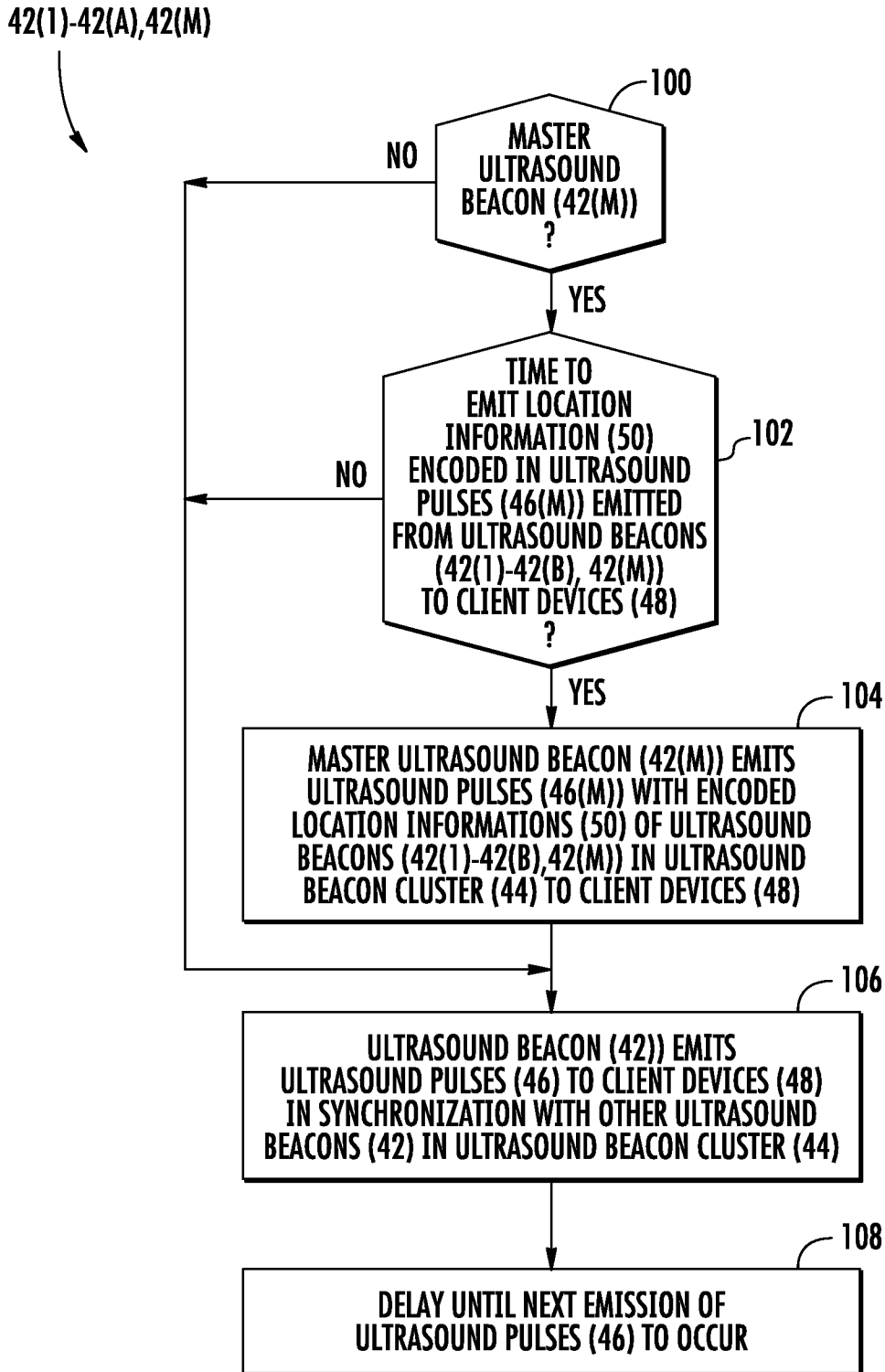


FIG. 6

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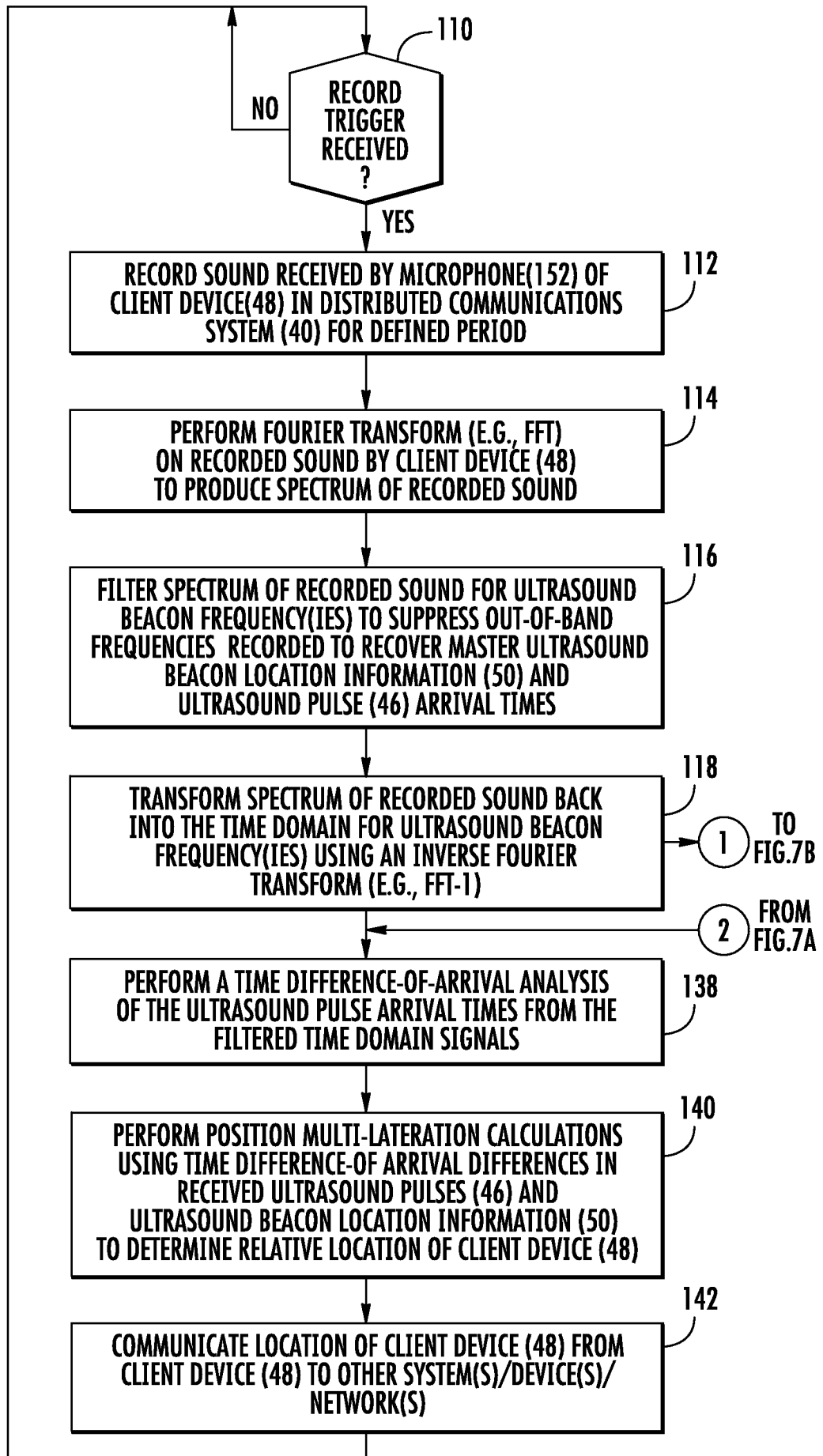


FIG. 7A

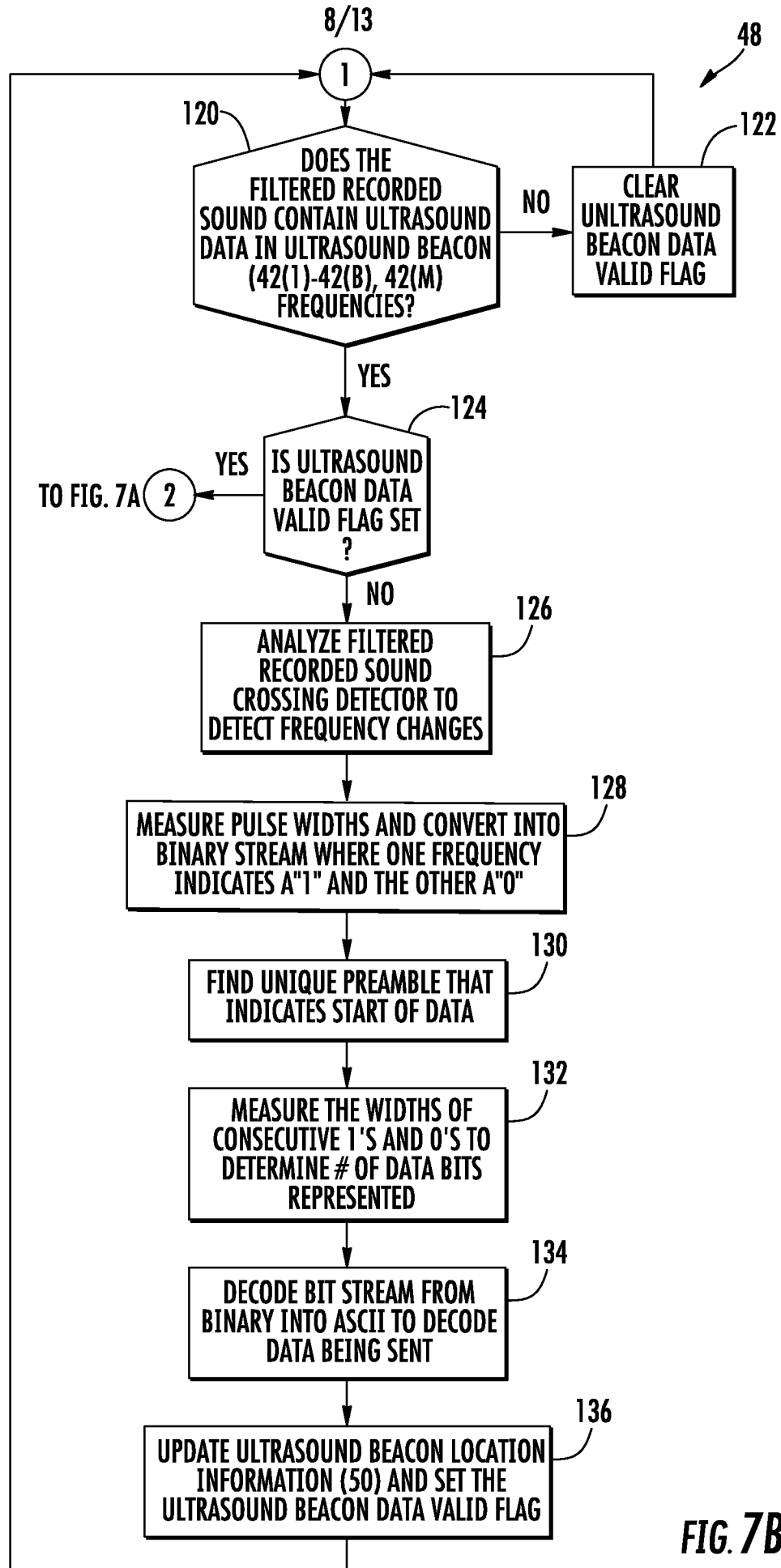


FIG. 7B

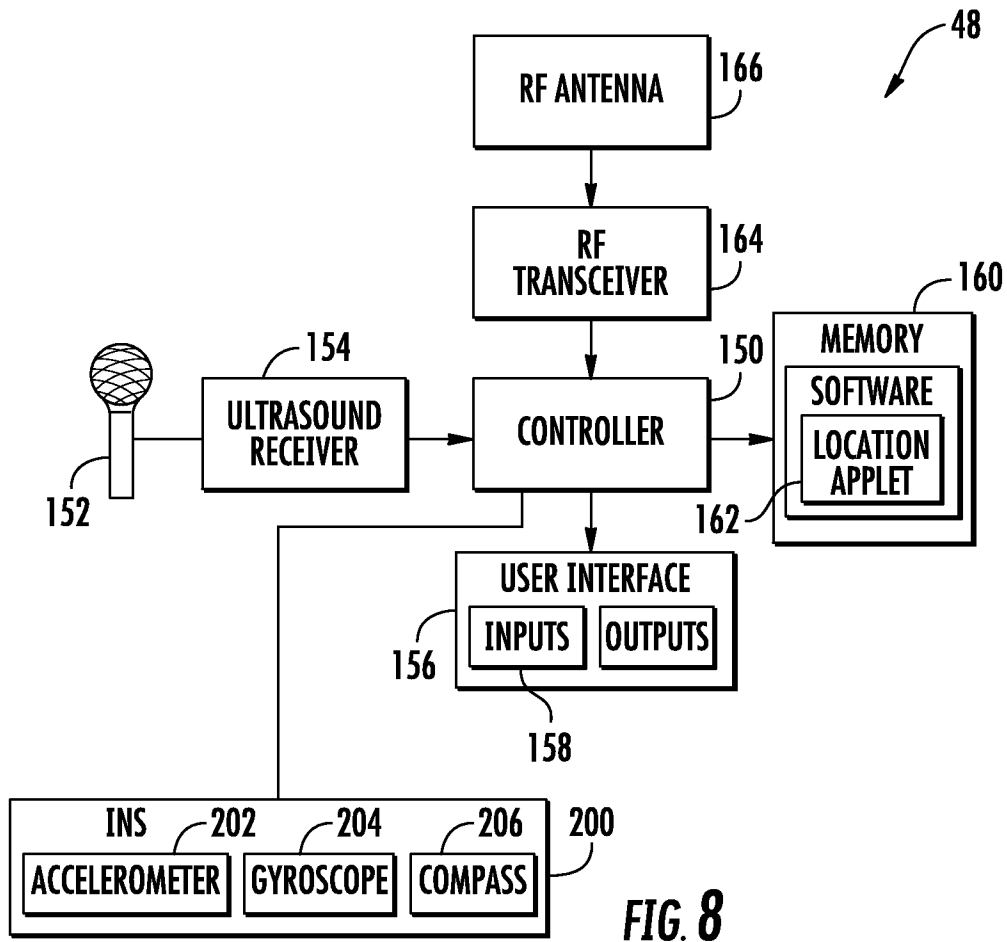


FIG. 8

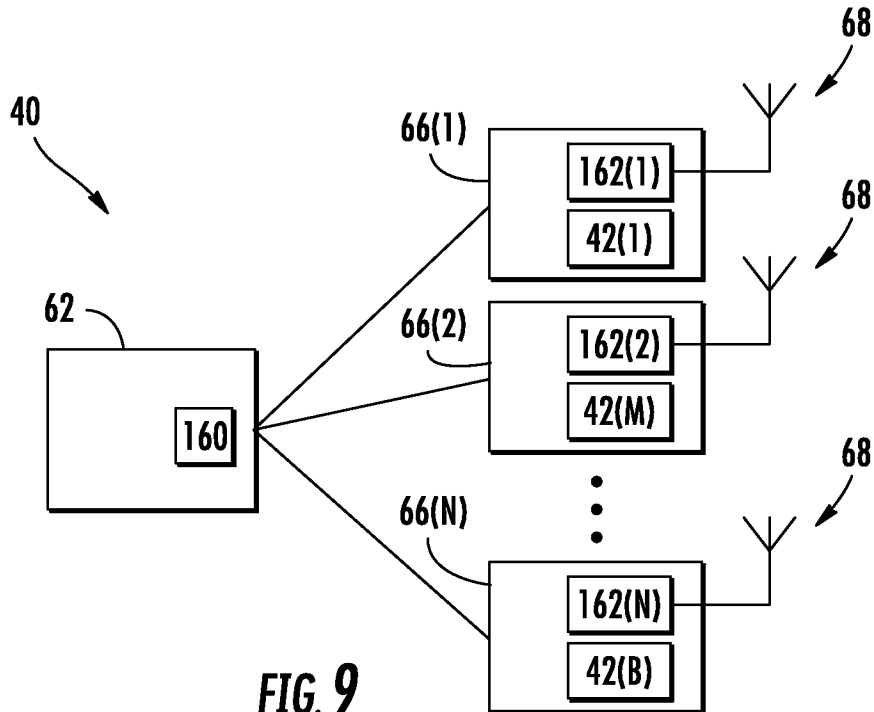


FIG. 9

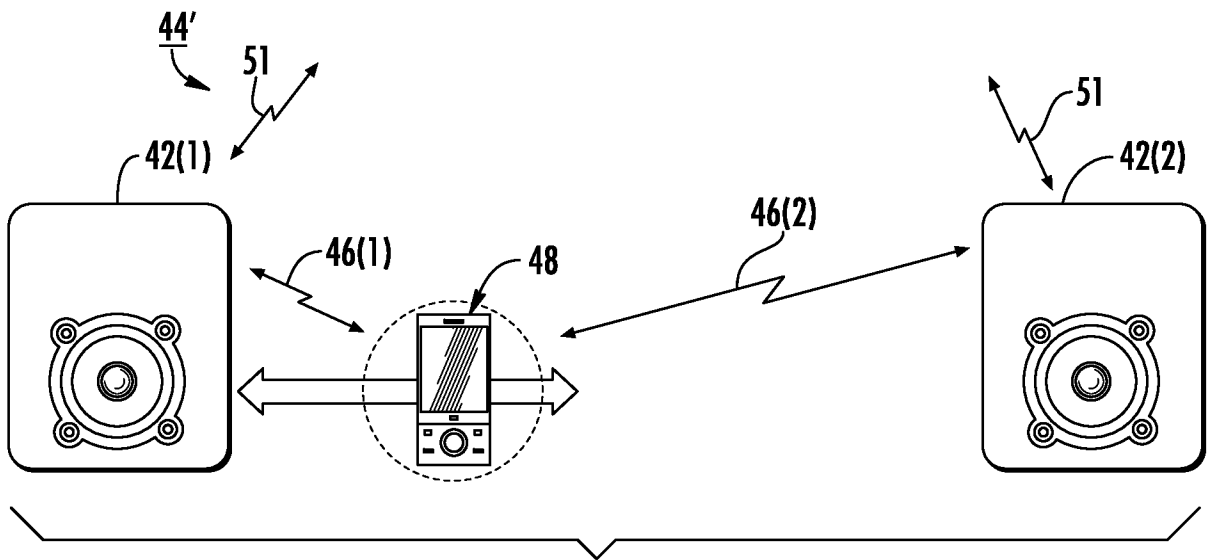


FIG. 10

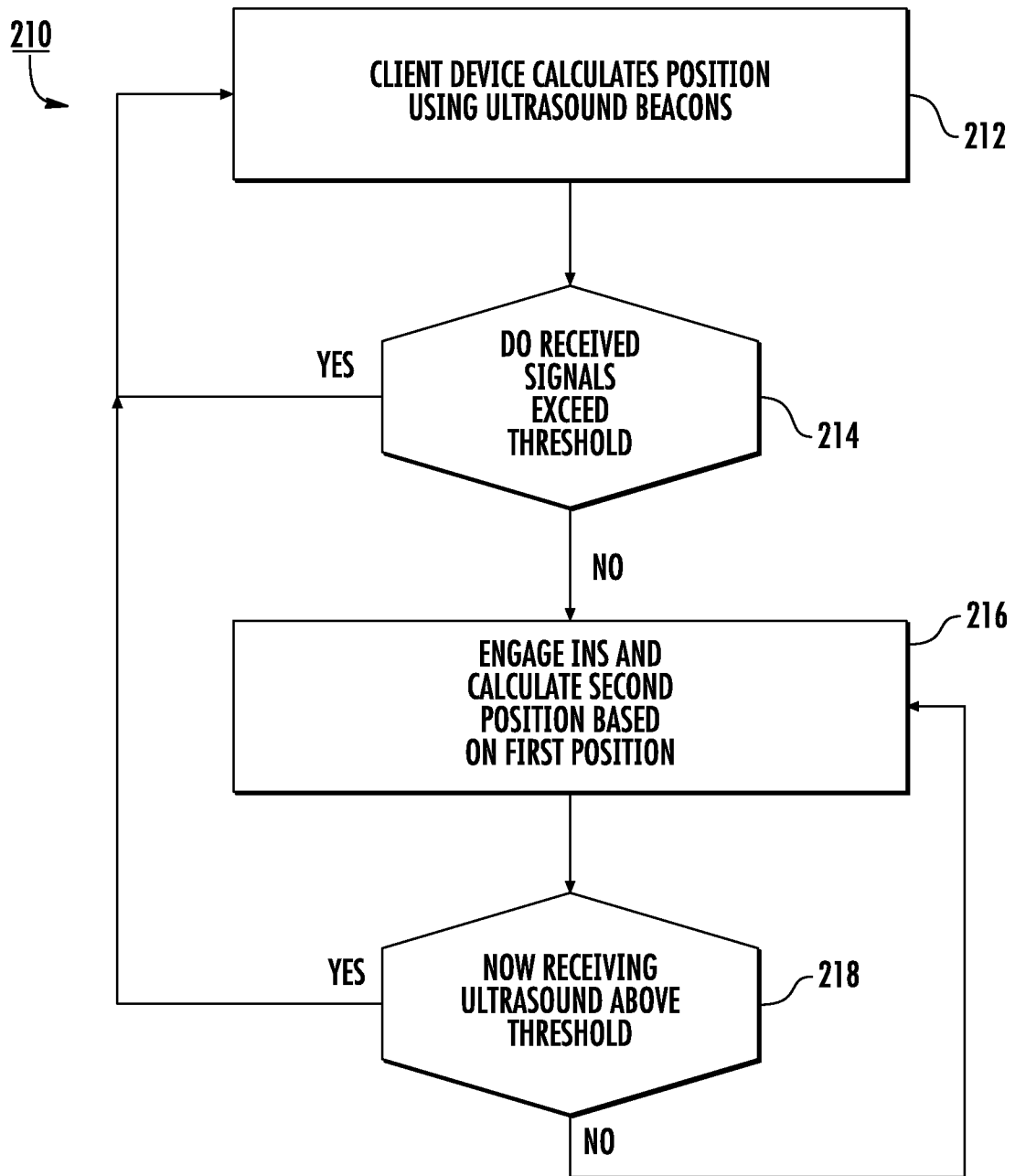


FIG. 11

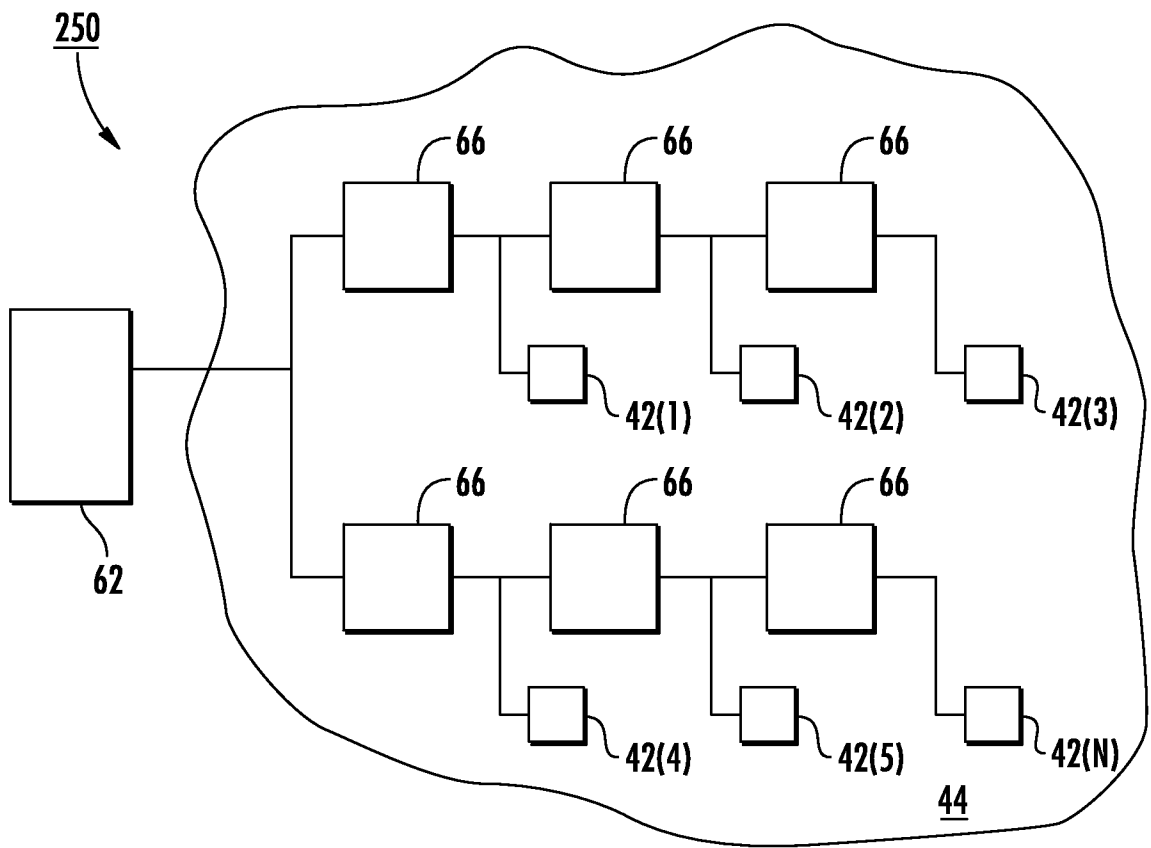


FIG. 12

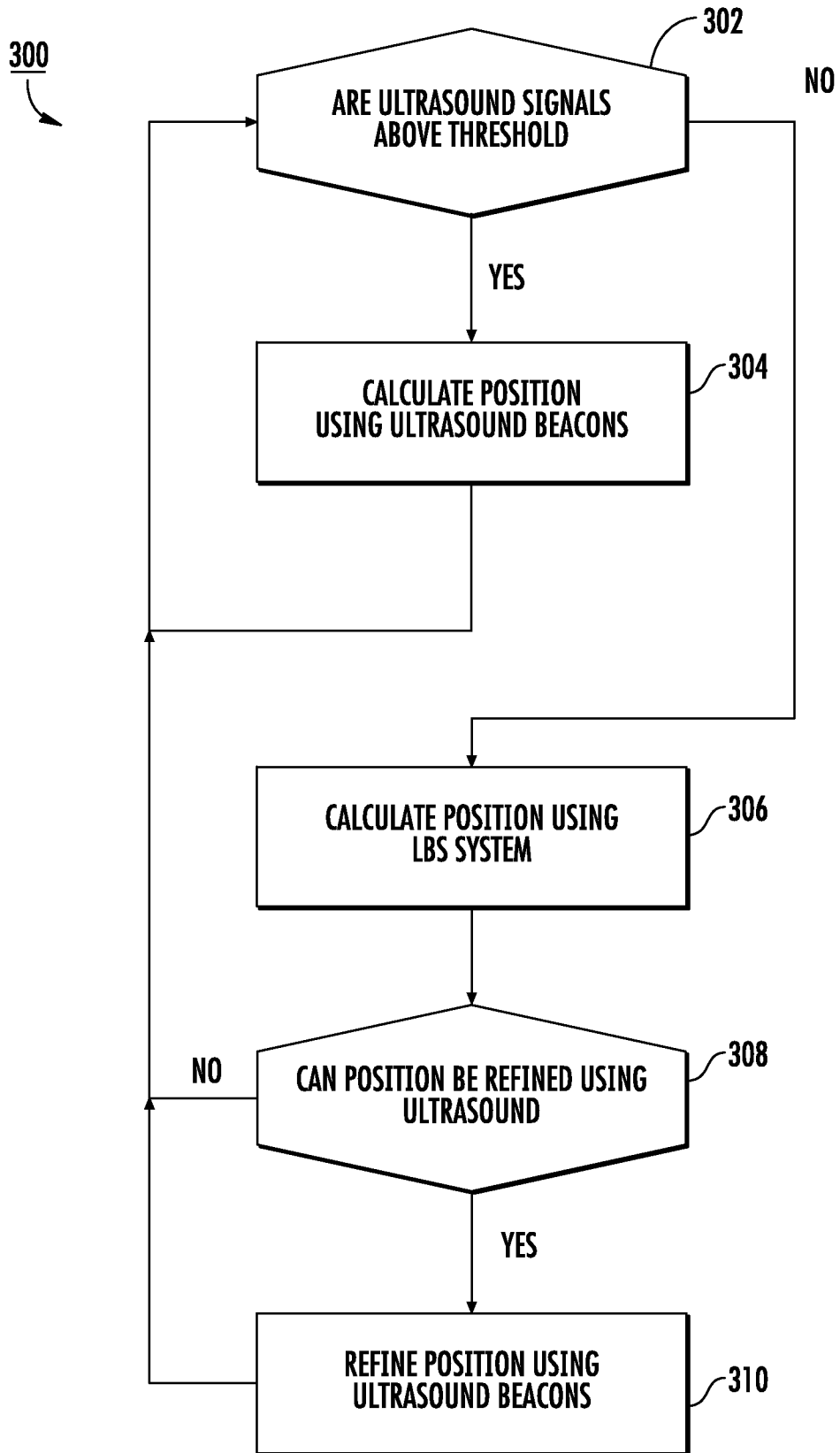


FIG. 13

INTERNATIONAL SEARCH REPORT

International application No PCT/US2013/043107

A. CLASSIFICATION OF SUBJECT MATTER INV. G01S5/18 G01S5/26 G01S5/02 G01S1/80 ADD.				
According to International Patent Classification (IPC) or to both national classification and IPC				
B. FIELDS SEARCHED				
Minimum documentation searched (classification system followed by classification symbols) G01S H04W				
Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched				
Electronic data base consulted during the international search (name of data base and, where practicable, search terms used) EPO-Internal, WPI Data, INSPEC, COMPENDEX				
C. DOCUMENTS CONSIDERED TO BE RELEVANT				
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.		
X	AU 2010 100 320 A4 (CELLTEK ELECTRONICS PTY LTD) 17 June 2010 (2010-06-17) the whole document -----	1-37		
A	US 2010/309752 A1 (LEE HYONG EUK [KR] ET AL) 9 December 2010 (2010-12-09) claim 1 -----	1-27		
A	US 2012/108258 A1 (LI XINTIAN [US]) 3 May 2012 (2012-05-03) abstract figure 2 paragraphs [0021], [0022] -----	28-37		
<input type="checkbox"/> Further documents are listed in the continuation of Box C. <input checked="" type="checkbox"/> See patent family annex.				
* Special categories of cited documents : <table style="width: 100%; border: none;"> <tr> <td style="width: 50%; border: none; vertical-align: top;"> "A" document defining the general state of the art which is not considered to be of particular relevance "E" earlier application or patent but published on or after the international filing date "L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified) "O" document referring to an oral disclosure, use, exhibition or other means "P" document published prior to the international filing date but later than the priority date claimed </td> <td style="width: 50%; border: none; vertical-align: top;"> "T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention "X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone "Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art "&" document member of the same patent family </td> </tr> </table>			"A" document defining the general state of the art which is not considered to be of particular relevance "E" earlier application or patent but published on or after the international filing date "L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified) "O" document referring to an oral disclosure, use, exhibition or other means "P" document published prior to the international filing date but later than the priority date claimed	"T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention "X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone "Y" document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art "&" document member of the same patent family
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Date of the actual completion of the international search 30 August 2013	Date of mailing of the international search report 09/09/2013			
Name and mailing address of the ISA/ European Patent Office, P.B. 5818 Patentlaan 2 NL - 2280 HV Rijswijk Tel. (+31-70) 340-2040, Fax: (+31-70) 340-3016	Authorized officer Ó Donnabháin, C			

INTERNATIONAL SEARCH REPORT

Information on patent family members

International application No
PCT/US2013/043107

Patent document cited in search report	Publication date	Patent family member(s)	Publication date
AU 2010100320	A4	17-06-2010	NONE

US 2010309752	A1	09-12-2010	KR 20100131682 A 16-12-2010
			US 2010309752 A1 09-12-2010

US 2012108258	A1	03-05-2012	NONE
