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Demo Abstract: A Testbed for Long-Range LoRa Communication

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ABSTRACT
Designing and testing low-power wireless communication protocols often requires experimental deployments on real hardware in realistic settings. Infrastructure testbeds have the advantage that they allow reproducible results using different network configurations. However, most testbeds are either in- or outdoor only and do not span long and short ranges at the same time. In this work, we present an extension to the popular FlockLab testbed on a campus-scale in order to better support testing of long-range communication, for example using the LoRa modulation. Different to existing LoRa test networks where specific protocol layers are fixed, we support custom modification above the physical hardware (above PHY) which allows the development and testing of alternative full custom MAC layers that are not based on LoRaWAN.

CCS CONCEPTS
• Networks → Wide area networks; Sensor networks.

KEYWORDS
LoRa, long-range, testbed, FlockLab, time synchronization

ACM Reference Format:

1 MOTIVATION
Testbeds for wireless communication protocols are useful when developing and testing protocols since it reduces the effort to deploy test networks repeatedly [10]. Furthermore, such a testbed improves the reproducibility of experiments and allows to share infrastructure [5]. Contrary to many other testbeds, FlockLab [2, 6] has always supported a mix of in- and outdoor placements. However, all nodes were located in rather close proximity to each other in and around an office building. This setup has been vastly popular: the FlockLab testbed has been operated since 2012, run over 53822 tests by 325 distinct users and reached an average annual utilization of over 55%. In recent years, long-range communication for IoT applications has become increasingly important. Although publicly accessible test networks for long-range protocols exist (e.g. e.g. TheThingsNetwork[3] for LoRa), they are only of limited use for designing and testing on the lower layers since modifications of the fixed MAC layer implementation are typically not possible. To the best of our knowledge, sensor network testbeds that support both long-range communication and and provide the option to monitor and control communication layers above the physical hardware do not exist. Therefore, we are currently extending the existing short baseline distances in FlockLab by adding additional nodes on rooftop locations and with significantly larger spacing. The vision is to extend FlockLab to span the whole campus (≤ 1 km link distance) or even parts of the city (5–10 km). Similar efforts have been made for 802.11b/g mesh network research at MIT with the RoofNet [4].

2 FLOCKLAB SYSTEM SETUP
The FlockLab testbed consists of observer nodes and a backend server. Each observer node can host 4 targets (devices under test), that are modules with radio and microcontroller chips used for wireless protocol development. The observer provides the infrastructure to power, program, stimulate, log and profile the targets. When running a test on FlockLab, the server instructs the observers to setup and start the targets. While the test is running, the observers independently collect profiling data which they aggregate and send to the server once the test is finished. Users can then access all test data which is stored in a database on the server.

Topology: Currently, the extended FlockLab testbed consists of 28 nodes located on a single floor inside an office building (75 × 35 m) and 2 rooftop nodes located up to 470 m away (see Figure 1).

![Figure 1: FlockLab testbed extension to rooftop nodes.](image-url)

Figure 1: FlockLab testbed extension to rooftop nodes.

Services and Time Synchronization: For designing and testing low-power wireless network protocols, FlockLab offers the services listed in Table 1. The GPIO services provides access to up to 5 GPIO pins of the target. This allows to observe or initiate state changes or measure duty-cycles with high accuracy. The power profiling allows to perform fine-grained power measurements. Serial output of the target is logged by the serial tracing service. Interaction via the serial interface is supported by the serial forwarder service. Both the GPIO and the power profiling services provide high temporal accuracy which is required for developing low-power wireless protocols on the lower layers of the network stack.

The time synchronization of the original FlockLab testbed uses a custom wireless time synchronization protocol based on Glossy [7].
Observer
Glossy
wired) between two observers using different time synchronization
This allows to select different antennas for individual tests.
Therefore, each rooftop node is equipped with a dedicated GPS
(GlossySync) referenced to a 1 Pulse-per-second (PPS) signal sourced
from a ublox LEA-6T GPS receiver (see left part of Figure 2). This
provides an offset between two observers below 1 μs which is suffi-
cient for most applications. However, recent work incorporating
the time-of-flight of radio signals has shown that higher accuracy
is required [8] and FlockLab has been outfitted temporarily with
extra GPS receivers in order to perform these tests. This experience
and the fact that it is not possible to extend the currently used
short-range GlossySync time synchronization required a different
approach. The option to use PTP over Ethernet [1] (accuracy <1 μs)
have been explored but not implemented since it would require spe-
cialized hardware and infrastructure on the networking segment.
Therefore, each rooftop node is equipped with a dedicated GPS
receiver providing a 1 PPS signal directly to the FlockLab observer.
Since the used reference timebase (GPS) is the same for both sys-
tems, we only need to make sure that the offset between GlossySync
and GPS is properly compensated. Measurements of the resulting
time difference when timestamping the same GPIO event (hard
wired) between two observers using different time synchronization
methods are listed in Table 2.

<table>
<thead>
<tr>
<th>FlockLab Service</th>
<th>Max. Rate</th>
<th>Time Sync</th>
</tr>
</thead>
<tbody>
<tr>
<td>GPIO tracing</td>
<td>10 MHz</td>
<td>GlossySync/GPS</td>
</tr>
<tr>
<td>GPIO actuation</td>
<td>10 MHz</td>
<td>GlossySync/GPS</td>
</tr>
<tr>
<td>Power profiling</td>
<td>28 ksamples/s</td>
<td>GlossySync/GPS</td>
</tr>
<tr>
<td>Serial tracing</td>
<td></td>
<td>NTP</td>
</tr>
<tr>
<td>Serial forwarding</td>
<td></td>
<td>–</td>
</tr>
</tbody>
</table>

Table 1: FlockLab requires tight time synchronization.

<table>
<thead>
<tr>
<th>Mean</th>
<th>Std dev.</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.016 μs</td>
<td>0.202 μs</td>
</tr>
<tr>
<td>0.692 μs</td>
<td>0.206 μs</td>
</tr>
<tr>
<td>0.050 μs</td>
<td>0.115 μs</td>
</tr>
</tbody>
</table>

Table 2: FlockLab time synchronization performance.

3 DEMONSTRATION SETUP
In this demonstration, we will show the FlockLab hardware setup
(observer with targets) as well as demonstrate running tests on
both short-range radio architectures (TinyNode, TmoteSky, DPP2-
CC430) as well as long-range radio architectures (DPP2-SX1262).
Furthermore, a visualization of the resulting GPIO traces can be
observed. The DPP2-CC430 and DPP-SX1262 are based on the Dual
Processor Platform (DPP1) [9].

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1See a separate DPP-related demo submission to IPSN 2019.