

Multilateration

Previous derivations on this topic were made in years passed to enable calculations with limited numbers of hydrophone channels. This page provides a generalized algorithm for locating a pinger in 3D in a robust, linear manner with an arbitrary number of arbitrarily placed hydrophones. This solution is an unambiguous, precise result that evaluates at all distances and does not require that the signal originate in the far-field.

This method of calculation requires 5 or more hydrophones. Substituting a depth sensor for one of the required hydrophones is possible, and covered below. The submarine does *not* need to be held level to make use of the depth sensor.

The exact math to implement for the solution can be found by scrolling directly to the bottom of this page.

Problem Setup

Apart from a minimum number of hydrophones, there are no constraints on the set-up of the system. One hydrophone h_0 is used as a reference and lies at the origin by definition. A second hydrophone h_1 serves as a static reference point against the origin hydrophone. It may still be placed at an arbitrary location. All other hydrophones h_n for $n > 1$ are evaluated against these two hydrophones.

h_0 is at location $h_0 = (0,0,0)$

h_1 is at location $h_1 = (x_1, y_1, z_1)$

h_n is at location $h_n = (x_n, y_n, z_n)$

The ping source is at location $p_{\text{pinger}} = (X, Y, Z)$

When a ping is received by the hydrophones, the hardware outputs differences in time-of-arrival from the origin, Δt_n , which corresponds to the difference in time between when the ping was received by h_0 and h_n , which is a function of their pathlengths to the pinger.

$$\Delta t_n = \frac{\sqrt{(X-x_n)^2 + (Y-y_n)^2 + (Z-z_n)^2} - \sqrt{X^2 + Y^2 + Z^2}}{c_s}$$

These time differences Δt_n are multiplied by the speed of sound c_s (~1500m/s) to find path-length differences Δr_n

$$\Delta r_n = \Delta t_n * c_s = \sqrt{(X-x_n)^2 + (Y-y_n)^2 + (Z-z_n)^2} - \sqrt{X^2 + Y^2 + Z^2}$$

With these measured values, $x_n, y_n, z_n, \Delta r_n$, for each hydrophone, we can fill in all values for the linear expression between our measurements, and the position of the pinger (X, Y, Z) .

Linear Equation

The linear equation takes the form:

$$R^T * X_{\text{global}} = X_{\text{local}} = A^{-1}(C-B)$$

Therefore:

$$X_{\text{global}} = RA^{-1}(C-B)$$

Which is our desired solution. Working backwards, we can also properly write the linear system for each individual hydrophone as: $A_n R^T X_{\text{global}} = (C_n - B_n)$

Depth Sensor Substitution

Now that the evaluation of (X, Y, Z) is part of a linear system, it is easy to see how direct measurements of any of the states can substitute for hydrophone measurements.

$$\begin{bmatrix} A_{x2} & A_{y2} & A_{z2} \\ A_{x3} & A_{y3} & A_{z3} \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \end{bmatrix} = \begin{bmatrix} C_2 \\ C_3 \\ z_{\text{pinger}} \end{bmatrix} - \begin{bmatrix} B_2 \\ B_3 \\ z_{\text{sub}} \end{bmatrix}$$

Which requires only 4 hydrophones, $h_0, h_1, h_2,$ and h_3 plus the depth sensor measuring z_{sub} to compared against the known depth of the pinger z_{pinger} .

However, the depth sensor will always measure the absolute depth of the submarine regardless of the submarine's orientation $R(\psi, \phi, \theta)$. Thus the difference measured will always be $z_{\text{pinger}} - z_{\text{sub}} = Z_{\text{global}}$.

Thus in order to properly set up the system, we must use the formula derived in the Rotation section:

$$A_n R^T X_{\text{global}} = (C_n - B_n)$$

Which properly applied gives us the full equation:

$$\begin{bmatrix} A_{x2} & A_{y2} & A_{z2} \\ A_{x3} & A_{y3} & A_{z3} \end{bmatrix} * \begin{bmatrix} R \end{bmatrix}^T \begin{bmatrix} 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} X \\ Y \\ Z \end{bmatrix} = \begin{bmatrix} C_2 \\ C_3 \\ z_{\text{pinger}} \end{bmatrix} - \begin{bmatrix} B_2 \\ B_3 \\ z_{\text{sub}} \end{bmatrix}$$

Which finally lets us calculate the full solution:

Full Solution

$$\begin{bmatrix} X \\ Y \\ Z \end{bmatrix} = \begin{bmatrix} A_{x2} & A_{y2} & A_{z2} \\ A_{x3} & A_{y3} & A_{z3} \end{bmatrix} * \begin{bmatrix} R \end{bmatrix}^T \begin{bmatrix} 0 & 0 & 1 \end{bmatrix}^{-1} \left(\begin{bmatrix} C_2 \\ C_3 \\ z_{\text{pinger}} \end{bmatrix} - \begin{bmatrix} B_2 \\ B_3 \\ z_{\text{sub}} \end{bmatrix} \right)$$

With polar bearings:

$$\text{Azimuth} = \arctan\left(\frac{Y}{X}\right), \quad \text{Inclination} = \arctan\left(\frac{Z}{\sqrt{X^2 + Y^2}}\right), \quad \text{Range} = \sqrt{X^2 + Y^2 + Z^2}$$

given: $R = R(\psi, \phi, \theta)$, $\Delta r_n = \Delta t_n * c_s$, $h_n = (x_n, y_n, z_n)$
 $A_{xn} = \det \begin{vmatrix} 2x_1 & 2x_n \\ \Delta r_1 & \Delta r_n \end{vmatrix}$, $A_{yn} = \det \begin{vmatrix} 2y_1 & 2y_n \\ \Delta r_1 & \Delta r_n \end{vmatrix}$, $A_{zn} = \det \begin{vmatrix} 2z_1 & 2z_n \\ \Delta r_1 & \Delta r_n \end{vmatrix}$, $B_n = \det \begin{vmatrix} \Delta r_1^2 & \Delta r_n^2 \\ \Delta r_1 & \Delta r_n \end{vmatrix}$, $C_n = \det \begin{vmatrix} (x_1^2 + y_1^2 + z_1^2) & (x_n^2 + y_n^2 + z_n^2) \\ \Delta r_1 & \Delta r_n \end{vmatrix}$

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