

Multi-User Detection using Support Vector Machines

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ABSTRACT

In this paper, support vector machines (SVM) are applied to multi-user detector (MUD) for direct sequence (DS)-CDMA system. This work shows an analytical performance of SVM based multi-user detector with some of kernel functions, such as linear, sigmoid, and Gaussian. The basic idea in SVM based training is to select the proper number of support vectors by maximizing the margin between two different classes. In simulation studies, the performance of SVM based MUD with different kernel functions is compared in terms of the number of selected support vectors, their corresponding decision boundary, and finally the bit error rate. It was found that controlling parameter C , in SVM training have an effect, in some degree, to SVM based MUD with both sigmoid and Gaussian kernel. It is shown that SVM based MUD with Gaussian kernels outperforms those with other kernels.

Key Words : Multiuser, Detector, DS-CDMA, Support Vector Machine, Neural Network

I. Introduction

Direct-sequence code division multiple access (DS-CDMA) has emerged as the preferred techniques for increasing the channel capacity through multiple access communication systems, because the whole frequency band is used all the time and bandwidth can be utilized more efficiently. In a DS-CDMA system, the objective of the receiver is to detect the transmitted information bits of one (at mobile-end) or many (at base station) users. A variety of MUD has been proposed for DS-CDMA systems. Generally, the linear minimum mean square error (MMSE) MUD is widely used, as it is computationally very simple and can readily be implemented using standard adaptive filter techniques^[1-2]. The conventional linear detectors, however, fail to achieve good performance when channel suffers from high levels of additive noise or highly nonlinear distortion, or when the signal-to-noise ratio is poor. The linear detector can only work

when the underlying noise-free signal classes are linearly separable with the introduction of proper channel delays, where the channel is assumed to be stationary. In reality, the mobile channels are going to be non-stationary where it is hard to determine the proper channel delay that varies with time. If proper channel delay is not introduced in linear MUD, the signal classes from the channel output states will be non-linearly separable.

In order to get around this problem, neural network technology has been considered in implementing MUD, because it has the capability of recovering the originally transmitted signals from nonlinear decision boundary cases^[3-7]. In fact, neural networks have received much attention from a variety of fields, especially for telecommunication systems, because of its characteristics, such as inherent parallelism, noise immunity, knowledge storage, adaptability, and pattern classification capability^[3-9].

Aazhang et al.^[3] first reported a study of

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the $M \times 1$ vector. $\mathbf{u} = [\mathbf{u}_1, \dots, \mathbf{u}_N]$ denotes the normalized user code matrix, and the diagonal user signal amplitude matrix is given by $\mathbf{A} = \text{diag}\{A_1, \dots, A_N\}$. The channel inter-symbol interference span P depends on the channel order q and the chip sequence length M : $P=1$ for $q=0$, $P=2$ for $0 < q \leq M-1$, $P=3$ for $M-1 < q \leq 2M-1$ and so on.

Considering the third part in (3), the user symbol vectors, \mathbf{S}_k , the number of user, N and the number of interference span, P , there are $N_s = 2^{NP}$ possible combinations of the channel input sequence. Here \mathbf{S}_k^j is represented as

$$\mathbf{S}_k^j = [\mathbf{s}_k^j, \mathbf{s}_{k-1}^j, \mathbf{s}_{k-2}^j, \dots, \mathbf{s}_{k-P+1}^j]^T, 1 \leq j \leq N \quad (4)$$

This produces 2^{NP} values of the noise-free channel output vector

$$\mathbf{r}_k = [r_k, r_{k-1}, \dots, r_{k-M+1}]^T \quad (5)$$

These vectors will be referred to as the desired channel states, and they can be partitioned into two classes according to the corresponding value in \mathbf{S}_k^j , depending on which user is considered in making decision (here no channel delay is assumed

$$\left. \begin{aligned} R_i^+ &= \{ \hat{\mathbf{r}}_k \mid s_{i,k} = 1 \}, \\ R_i^- &= \{ \hat{\mathbf{r}}_k \mid s_{i,k} = -1 \}, \end{aligned} \right\} \quad (6)$$

Once all the channel output states and corresponding desired state are determined, these values can be used Bayesian classification solution as follows

$$F(\mathbf{r}_k) = \sum_{j=1}^N \frac{\tau_j s_i^j}{\sqrt{2\pi}\sigma} \exp\left(-\frac{\|\mathbf{r}_k - \hat{\mathbf{r}}_k^j\|^2}{2\sigma^2}\right) \quad (7)$$

where $\hat{\mathbf{r}}_k^j$ is the noise-free received signal states, τ_j are *a priori* probability of $\hat{\mathbf{r}}_k^j$, and the σ^2 are the noise variance.

III. SVM MUD

3.1 Introduction to SVM

The support vector machine (SVM) has been developed by Vapnik^[10] and obtained popularity due to many promising features such as better empirical performance. The basic idea behind SVM technique is to maximize the margin, either side of a hyperplane separating the classes. An optimum separating hyperplane can be found by minimizing the squared norm of the separating hyperplane. The minimization can be formulated as a convex quadratic programming (QP) problem, in which the training data are represented as a matrix of inner products between feature vectors. Once the optimum separating hyperplane is found, data points that lie on its margin are known as support vector points and the solution is an expansion on these points only. Other points can be ignored as shown in Fig. 2.

The major advantage of using SVM is that a nonlinear SVM can be easily obtained by using kernel functions. In that way the nonlinear classification problem can be changed to linear classification problem.

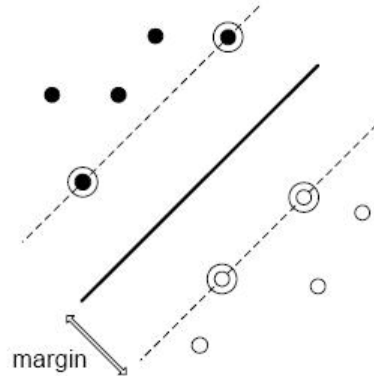


Fig. 2. SVM separation of two classes-SV points circled

3.2 SVM Detector and Kernel Functions

Generally the receiver can have access to a block of L training samples as follows

$$R = \{\mathbf{r}_j, 1 \leq j \leq L\} \quad (8)$$

and the set of corresponding class labels is arranged as the following equation

$$D = \{\mathbf{d}_j, 1 \leq j \leq L\} \quad (9)$$

Considering the standard SVM method, an SVM detector can be constructed for user i ,

$$F_{svm}(\mathbf{r}_k) = \sum_{j=1}^L \alpha_j d_j K(\mathbf{r}_k, \mathbf{r}_j) + \tau \quad (10)$$

where

$$\boldsymbol{\alpha} = [\alpha_1, \alpha_2, \dots, \alpha_L]^T \quad (11)$$

is the set of Lagrangian multipliers and can be obtained from the following quadratic programming (QP)

$$\boldsymbol{\alpha} = \arg \min_{\boldsymbol{\alpha}} \left\{ \frac{1}{2} \sum_{j=1}^L \sum_{i=1}^L \alpha_i \alpha_j d_i d_j K(\mathbf{r}_k, \mathbf{r}_j) - \sum_{j=1}^L \alpha_j \right\} \quad (12)$$

with the constraints

$$0 \leq \alpha_j \leq C, \quad 1 \leq j \leq L, \quad \sum_{j=1}^L \alpha_j d_j = 0 \quad (13)$$

and τ is the offset constant which is usually determined from the so called “margin” support vectors and C is the user-defined parameter for controlling the tradeoff between model complexity and training error. In (12), the kernel function $K(\cdot)$ can be used in the following form

$$\begin{aligned} \text{Linear} : K(\mathbf{r}_k, \mathbf{r}_j) &= (\mathbf{r}_k, \mathbf{r}_j) \\ \text{Polynomial} : K(\mathbf{r}_k, \mathbf{r}_j) &= ((\mathbf{r}_k, \mathbf{r}_j) + 1)^d \\ \text{Gaussian} : K(\mathbf{r}_k, \mathbf{r}_j) &= \exp\left(-\frac{1}{2\sigma^2} \|\mathbf{r}_k - \mathbf{r}_j\|^2\right) \\ \text{Sigmoid} : K(\mathbf{r}_k, \mathbf{r}_j) &= \tanh(k(\mathbf{r}_k, \mathbf{r}_j) + \theta) \end{aligned} \quad (14)$$

The SVM based MUD constructs set of Support vectors, denoted by R

$$F_{svm}(\mathbf{r}_k) = \sum_{\mathbf{r}_j \in R} \alpha_j d_j K(\mathbf{r}_k, \mathbf{r}_j) \quad (15)$$

and making the decision of user i data with

$$\hat{s}_{i,k} = \text{sign}(F_{svm}(\mathbf{r}_k)) \quad (16)$$

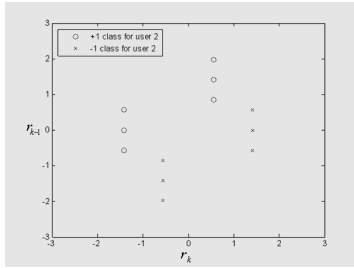
IV. Simulation Studies

Simulation studies were performed to compare different kernels based MUD. For the purpose of showing that multiuser detection can be regarded as a classification problem, a very simple two user system with 2 chips per symbol was considered. The chip sequences of the two users were set as (-1, -1) and (-1, 1), respectively. The following are channel impulse responses used in simulation

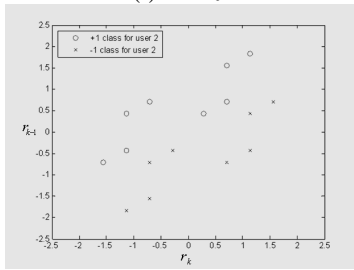
$$\left. \begin{aligned} H_1(z) &= 1 + 0.4z^{-1} \\ H_2(z) &= 0.8 + 0.5z^{-1} + 0.3z^{-2} \end{aligned} \right\} \quad (17)$$

The two users are assumed to have equal signal power. Simulation works consist of some procedures. The first is to estimate both noise free received signals and noise variances using supervised k -means clustering^[7]. The next one is to select the support vectors and to determine decision boundary based on kernel functions. Fig. 3 shows the distribution of noise-free signals for two different channel models above.

As shown in Fig. 4 and 5, SVM MUD with Gaussian kernel functions show reasonably better decision boundary than with other kernel functions. In the simulation studies, SVM with linear kernel functions didn't seem to be sensitive with controlling parameter, C , while SVM with both sigmoid and Gaussian did. It was found that in the sigmoid case, the margin was getting narrow with increase of C value. For Gaussian kernel functions, the number of selected support

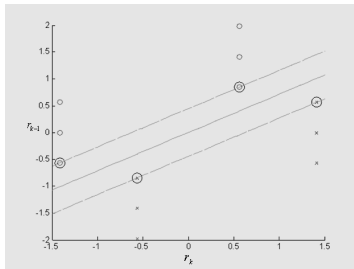


(a) $1+0.1z^{-1}$

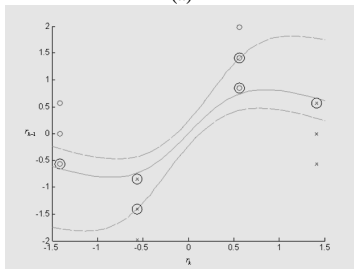


(b) $0.8+0.5z^{-1}+0.3z^{-2}$

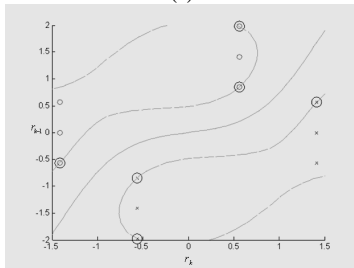
Fig. 3. Distribution of noise-free signals



(a)



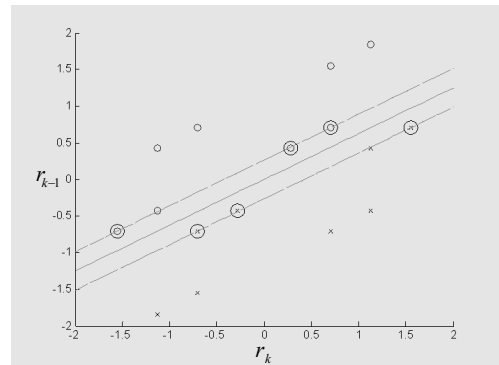
(b)



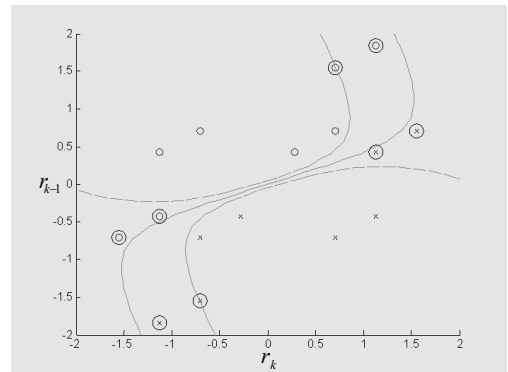
(c)

Fig. 4. Decision boundary with kernel functions. Circled points: selected support vectors $C=5$, (a) Linear, (b) Sigmoid, (c) Gaussian

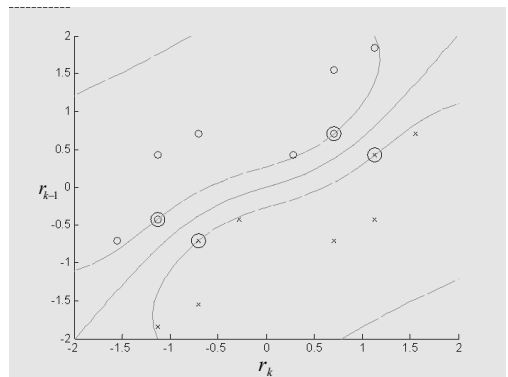
vectors (SVs) was varying: 10 SVs with $C=5$, 4 SVs with $C=10$ or 15, while changing the shape of decision boundary to the extent of selected SVs. In Fig. 6, the error rate performance was compared for two different channels. The bit error rate (BER) performance was conducted with 100,000 inputs with Gaussian noise. The variance



(a)



(b)



(c)

Fig. 5. Decision boundary with kernel functions. Circled points: selected support vectors $C=10$, (a) Linear, (b) Sigmoid, (c) Gaussian

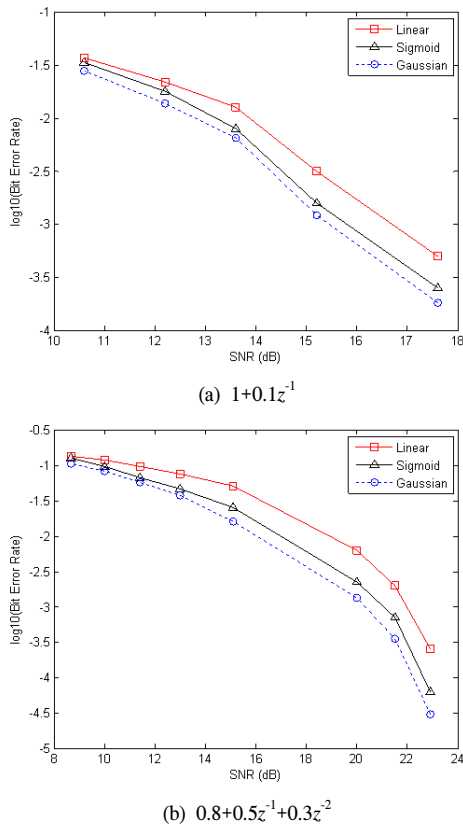


Fig. 6. A comparison of error rate performance

parameter, σ^2 used in Gaussian kernel functions is the same as noise variance estimated from k -means clustering techniques. As shown Fig. 6, the error rate performance of a SVM based MUD with Gaussian kernels outperforms with other kernels. This comes from the fact that the solution with Gaussian is approximately regarded as Bayesian optimal solution^[7].

V. Conclusion

The SVM based multiuser detector (MUD) described in this paper was investigated and analyzed with different kernel functions and SVM parameter. SVM MUD with linear kernels did not get influenced by controlling parameter, C . In contrast, SVM MUD with both sigmoid and Gaussian kernel functions changed the number of SVs and the corresponding decision boundary

when the different C values were used. Also, It was found that SVM based MUD with the Gaussian Kernels performed better than the linear or sigmoid kernels.

Research has been continuing into more complex cases with higher channel order, many users, and long chip sequences. In addition, the another SVM training technique, the sequential minimal optimization (SMO) will be investigated with different kernel functions, and its performance will be compared. Also, It is expected that the results of this study can be extended to various wireless cellular communication systems using multiple access schemes such as DS-CDMA, OFDM-CDMA, and multi-carrier CDMA.

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