

了 1 Mb/s,这是因为 AP3 比 AP1 的信道利用率低, AP2 比 AP4 信道利用率低,且剩余带宽都为 1.5 Mb/s,机器人分别关联 AP3 和 AP2,带宽都能得到满足.这和本文的算法的关联结果是一样的.在 [1, 65] 时间段内,相比于基于信道利用率的 AP 选择算法,本文算法使得机器人的平均通信带宽提高了 24%,这主要源自本文算法产生的切换时延较低.其它两个算法的平均通信带宽较低,与它们选择的 AP 和切换延时都有关系.

接下来,测试 AP 容量不同的情况.按照表 8 配置 AP 容量和网络中的数据流量,令服务器向指定的 4 个 STA 发送 UDP 流量.首先让机器人静止,测量在此配置下各个 AP 的 MAC 层传输速率,并计算出各自的应用层剩余带宽,如表 9 所示.

表 8 AP 容量和网络流量配置

流量源	流量目的地 (STA)	关联的 AP	AP 带宽 (Mb/s)	服务器发送速率 (Mb/s)
server	1	AP1	2	1.5
server	6	AP2	11	3.5
server	3	AP3	2	1
server	9	AP4	2	1.2

表 9 表 8 配置下的动态无线地图 (部分)(单位: Mb/s)

AP 列表	队列总长度	当前带宽 (物理层)	总带宽 (物理层)	剩余带宽 (应用层)
AP1	500	1.88	2	0.1
AP2	500	8.56	11	1
AP3	500	1.24	2	0.6
AP4	500	1.48	2	0.4

令机器人从起点向终点移动,服务器以 500 Kb/s 向机器人发送数据,测试不同的 AP 选择算法下机器人的平均通信速率,实验结果如图 7 所示,表 10 为不同算法选择的 AP 切换序列.

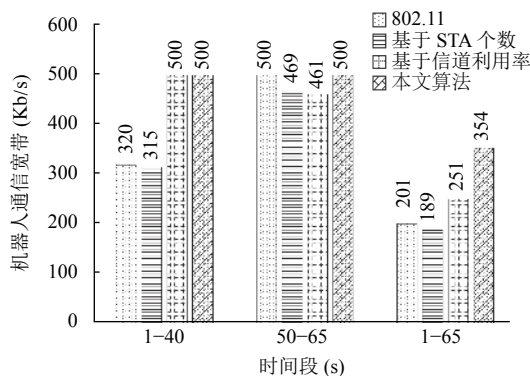


图 7 机器人在不同时间段内的平均通信带宽

使用 802.11 的 AP 选择算法,机器人在 [1, 40] 时间段内的平均通信带宽仅为 320 Kb/s,根据表 9, AP1 剩余带宽为 0.1 Mb/s,达不到机器人的带宽需求,从而机器人关联 AP1 后产生大量的丢包.在 [50, 65] 时间段内机器人接受带宽为 500 Kb/s,因为 AP2 剩余带宽为 1 Mb/s,能够满足机器人的带宽需求.使用基于 STA 个数的 AP 选择算法,机器人在 [1, 40] 和 [50, 65] 时间段内的平均通信带宽均未达到 500 Kb/s,由表 9 可知, AP1 和 AP4 虽然关联的 STA 个数最少,但是剩余带宽却是最低的,仅剩 0.1 Kb/s 和 0.4 Kb/s,无法满足机器人带宽需求.使用基于信道利用率的 AP 选择算法和本文算法,机器人在 [1, 40] 时间段内的平均通信带宽达到了需求的 500 Kb/s,此时两个算法都选择了 AP3,而 AP3 比 AP1 的信道利用率低,剩余带宽为 0.6 Mb/s,满足机器人的需求带宽,但是 [50-65] 时间段内,基于信道利用率的算法选择了 AP4,机器人通信带宽仅为 461 Kb/s,低于 500 Kb/s,由表 9 发现 AP4 无法满足机器人带宽需求.本文算法根据应用层剩余容量选择了 AP2,可以满足带宽需求.在 [1, 65] 时间段内,采用本文算法的机器人平均通信带宽最高,这是因为其它算法或者无法全程满足机器人的带宽需求,或者由于切换延时较高产生较多的丢包.

表 10 4 种 AP 选择算法产生的 AP 切换序列

AP 选择算法	AP 切换序列
802.11	{AP1, AP2}
基于 STA 个数	{AP2, AP4}
基于信道利用率	{AP3, AP4}
本文算法	{AP3, AP2}

综合以上实验可以看到,本文算法在切换延时和通信带宽保证方面均优于已有的 AP 切换算法.

5 总结

本文面向工业机器人场景提出了一种基于动态无线地图的带宽保证快速切换技术框架,并在网络仿真平台 NS3 上进行了实现和评估.与已有的 AP 切换算法相比,本文方法可以极大地减小机器人的切换延时,同时满足机器人的通信带宽需求.

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