

Range Measurements in an Open Field Environment

Design Note DN018

ABSTRACT

Range is one of the most important parameters of any radio system. Data rate, output power, receiver sensitivity, antennas, and the intended operation environment all influence the practical range of the radio link.

Contents

1	Introduction	2
2	Abbreviations	2
3	Path Loss and Propagation Theory	2
	3.1 Friis Equation	2
	3.2 Link Budget	3
	3.3 Ground Reflection (2-Ray) Model.....	3
	3.4 Noise	5
4	Validation Tests	6
	4.1 Friis Equation for Free Space	6
	4.2 Friis Equation With Ground Reflection	7
5	Summary	9
6	References	9

List of Figures

1	Transmission With Ground	3
2	Difference in Transmission Loss Due to Polarization	4
3	Multi-Path Fading	5
4	Measured and Simulated Signal Strengths	8
5	Gravel Football Pitch in the Town of Finstadbru.....	9

Trademarks

SmartRF is a trademark of Texas Instruments.
All other trademarks are the property of their respective owners.

1 Introduction

Range is one of the most important parameters of any radio system. Data rate, output power, receiver sensitivity, antennas, and the intended operation environment all influence the practical range of the radio link.

An open field is one of the simplest and most commonly used environments to do RF range tests. However here there are important effects to consider, and failing to address these often results in the test results being misinterpreted. This application report addresses non-ideal effects to consider when doing open field range measurements.

In this application report, the term "open field" means a large open area without any interfering radio sources (for example, a football field).

2 Abbreviations

EB: Evaluation board (SmartRF™04)

EM: Evaluation module

HW: Hardware (for example, the PCB or components)

LPW: Low-power wireless

PER: Packet error rate

SNR: Signal-to-noise ratio

TI: Texas Instruments

3 Path Loss and Propagation Theory

Communication is achieved through the transmission of signal energy from one location to another. The received signal energy must be sufficient to distinguish the wanted signal from the always present noise. This relationship is described as the required signal to noise ratio (S/N). The necessary SNR for a radio link is sometimes specified in receiver data sheets. More commonly the sensitivity is specified. This is the absolute signal level (S). When sensitivity is used, one assumes that only thermal noise is present and that the device is operated at room temperature. This chapter addresses the theory used to determine the range for radio systems in open and free-space environments.

3.1 Friis Equation

Range in radio communication is generally described by Friis equation (see [Equation 1](#)). This equation describes the dependency between distance, frequency (wavelength), antenna gain, and power.

$$P_R = P_T \frac{G_T G_R \lambda^2}{(4\pi)^2 d^n} \quad n = 2$$

where

- P_R = Power available from receiving antenna
- P_T = Power supplied to the transmitting antenna
- G_R = Gain in receiving antenna
- G_T = Gain in transmitting antenna
- λ = wavelength, where $\lambda = c/f$, c = speed of light, f = frequency
- d = Distance
- c = Speed of light in vacuum 299.972458×10^6 m/s

(1)

3.1.1 Using the Friis Equation

Equation 2 shows an example of using the Friis equation. In free space, the path loss is 80.2 dB over a 100-m distance when operating at 2.445 MHz.

In more typical applications, higher attenuation is expected, because an open field is one of the simplest environments.

$$P_R = P_T \frac{G_T G_R \lambda^2}{(4\pi)^2 d^n} = 1 \text{ mW} \times \frac{1 \times 1 \times \left(\frac{3 \times 10^8}{2445 \times 10^6} \right)^2}{(4\pi)^2 \times 100^2} = 9.532 \times 10^{-12} = -80.2 \text{ dBm} \quad (2)$$

3.2 Link Budget

The Friis equation is often referred to as the link budget. The difference between the received signal power, P_R , and the sensitivity of the receiver is referred to as the link margin. In a realistic link budget additional loss has to be added to the losses predicted by Friis equation. This application report addresses some of these losses in an open field environment. Range is the distance at which the link is operating with a signal level equal to the receiver sensitivity level. In digital radio systems sensitivity is often defined as the input signal level where PER exceeds 1%.

3.3 Ground Reflection (2-Ray) Model

In a typical radio link transmission waves are reflected and obstructed by all objects illuminated by the transmitter antenna. Calculating range in this realistic environment is a complex task requiring huge computing resources. Many environments include some mobile objects, adding to the complexity of the problem. Most range measurements are performed in large open spaces without any obstructions, moving objects, or interfering radio sources. This is primarily done to get consistent measurements. The Friis equation requires free space to be valid (see Section 3.1). Hand held equipment generally operates close to ground. This implies that ground influence has to be considered to do valid range calculations.

Figure 1 shows the situation with an infinite, perfectly flat ground plane and no other objects obstructing the signal. The total received energy can then be modeled as the vector sum of the direct transmitted wave and one ground reflected wave.

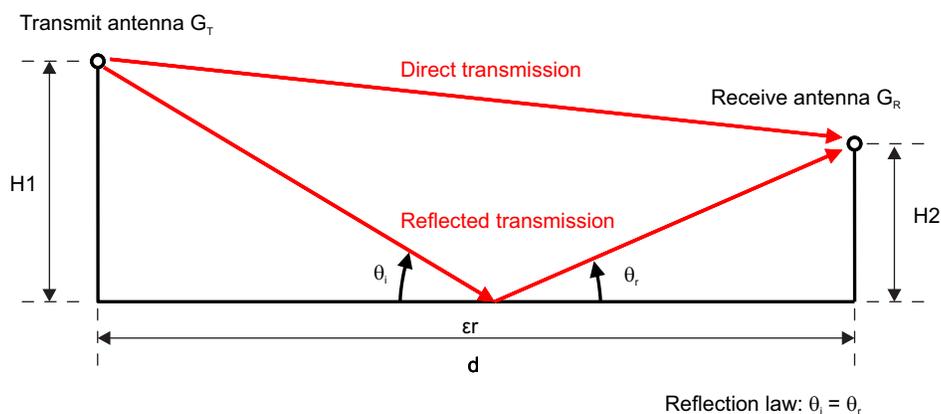


Figure 1. Transmission With Ground

The two waves are added constructively or destructively depending on their phase difference at the receiver. The magnitude and phase of the direct transmitted wave varies with distance traveled. The magnitude of the reflected wave depends on total traveled distance and the reflection coefficient (Γ) relating the wave before and after reflection.

3.3.1 Reflection Coefficient

Whenever an incident radio signal hits a junction between different dielectric media, a portion of the energy is reflected, while the remaining energy is passed through the junction. The portion reflected depend upon signal polarization, incident angle, and the different dielectrics (ϵ_r , μ_r , and σ). Assuming that both substances have equal permeability $\mu_r = 1$ and that one dielectric is free space, Equation 3 and Equation 4 are the Fresnel reflection coefficients for the vertical and horizontal polarized signals, respectively. [1]

$$\Gamma_V = \frac{(\epsilon_r - j60\sigma\lambda)\sin\theta_i - \sqrt{\epsilon_r - j60\sigma\lambda - \cos^2(\theta_i)}}{(\epsilon_r - j60\sigma\lambda)\sin\theta_i + \sqrt{\epsilon_r - j60\sigma\lambda - \cos^2(\theta_i)}} \tag{3}$$

$$\Gamma_h = \frac{\sin\theta_i - \sqrt{\epsilon_r - j60\sigma\lambda - \cos^2(\theta_i)}}{\sin\theta_i + \sqrt{\epsilon_r - j60\sigma\lambda - \cos^2(\theta_i)}} \tag{4}$$

The equations require some electrical data for the soil in the test environment. Reference [1] includes a table that lists ϵ_r and σ for some typical soil conditions. $\epsilon_r = 18$ and $\sigma = 0$ is used for all of the calculations in this application report.

For systems in which H1 and H2 are low compared to d, Equation 3 and Equation 4 can be simplified to $\Gamma_V = \Gamma_h = -1$. This simplification assumes that with low incident angle all of the energy is reflected. The phase change of the reflected wave is significant to the transmission budget (see Figure 2).

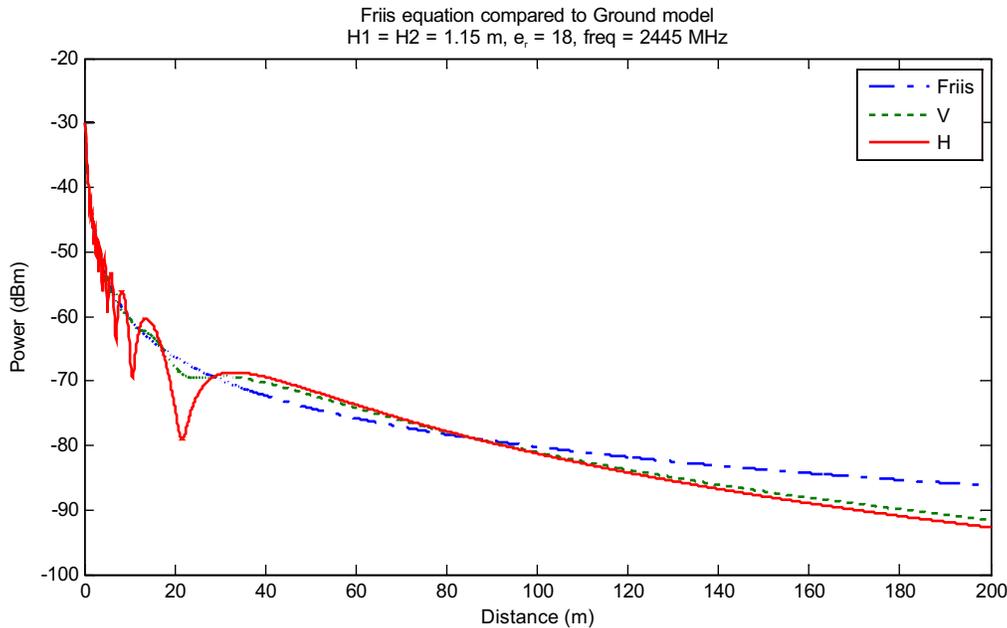


Figure 2. Difference in Transmission Loss Due to Polarization

Figure 2 shows the influence of polarization and ground in open field measurements. The values are calculated using the Matlab function in Section 4.2. The figure indicates a large difference between the Friis equation for free space and the expected performance when ground influence is included. Figure 2 also indicates that horizontal polarization (H) is more susceptible to multi-path fading than the vertical polarized signal (V). At long distances, the signal level including ground is considerably lower than predicted by the Friis equation. Finally, observe that vertically polarized signals have higher energy at long distance when compared to horizontally polarized signals.

NOTE: Many applications have strong cross-polarized components, making it difficult to separate between the polarizations. In this case, the actual signal level is often between the vertical and horizontal levels calculated as previously shown.

Figure 3 shows calculated values for a 2445-MHz horizontally polarized signal. The Friis equation for free space and the 500-kBaud sensitivity level is included in the figure for comparison. To measure the effective open field range for the CC2500 at this data rate, the typical process would be to start the EB PER test and then increase the distance between the two radio units.

The figure indicates that communication would be lost at approximately 35 m. Clearly the range potential is far greater. To identify this unused potential, the two units have to be separated by more than 39 m to regain communication. The location of this blind spot will vary with frequency, ground electrical characteristics and antenna elevation. It is however important to be aware of this during measurement to identify if the test has reached a local blind spot or the final range of the equipment. The difference between the level predicted by the Friis equation and the receiver sensitivity is often called the fade margin.

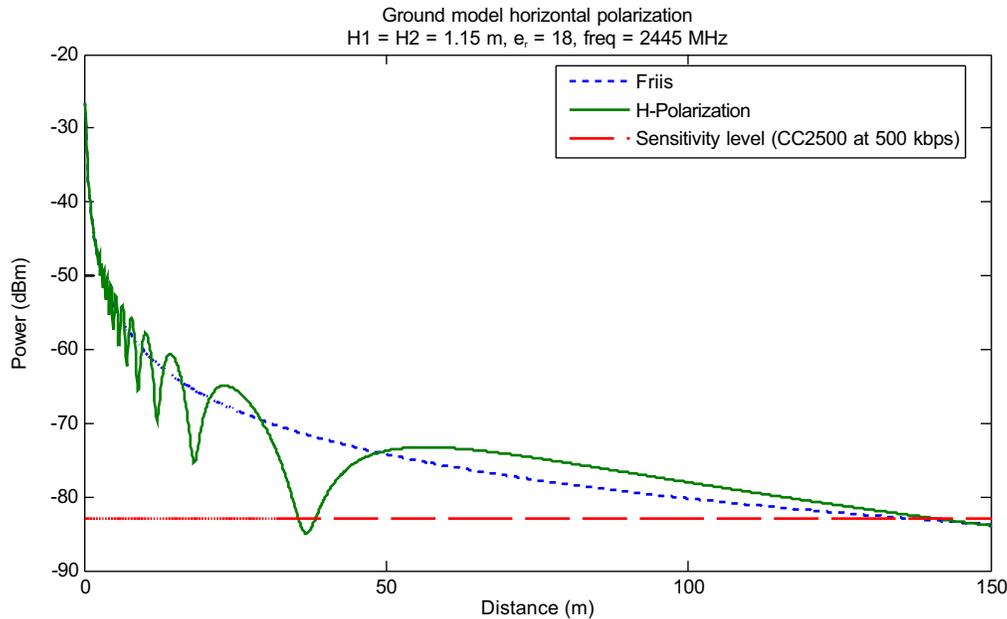


Figure 3. Multi-Path Fading

3.4 Noise

Noise is another important parameter when considering range. Noise can be categorized by its source. Thermal noise is noise generated by all objects due to its molecular thermal activities. Other radio traffic may be considered another form of noise. The noise from other electrical equipment is inherently difficult to describe in mathematical or statistical models. Equation 5 describes thermal noise.

$$v_n = \sqrt{\frac{4hfBR}{e^{kT} - 1}} \approx \sqrt{4kTBR} \quad [V_{rms}] \tag{5}$$

Temperature, effective noise bandwidth, and impedance determine the total thermal noise. At room temperature (300K, 27°C) this equation is often approximated by $-174 \text{ dBm} + 10\log_{10}(B)$, describing the situation with a perfect load match.

3.4.1 Thermal Noise

The CC2500 with 500 kBaud and $BW = 812.5 \text{ kHz}$ (recommended values) gives a room temperature noise floor at $-174 \text{ dBm} + 59.1 \text{ dB} = -114.9 \text{ dBm}$. The sensitivity is specified to be -83 dBm resulting in an SNR of 31.9 dB. An SNR of 31.9 dB is more than the demodulator requires, clearly indicating the potential range extension using an external LNA. (CC2500 has a simulated typical noise figure of approximately 16 dB).

Thermal noise is not a problem during range measurements. It should however be verified that the area used is free from other noise sources on the same frequency band. This could be done using a spectrum-analyzer (maximum hold) to look for noise sources before performing the test. This check should preferably be repeated at regular intervals during the test. Selecting a test area with low probability of interference is generally recommended. A picture of the test area used in the model validation tests can be seen in [Section 4.2.2](#).

4 Validation Tests

4.1 Friis Equation for Free Space

```
% friis_equation(Gt,Gr,f,n,d);
% This function is based on the theory in application report SWRA046
% This function calculates the propagation loss.
% path_loss_indoor =Gt·Gr·(C/(4·pi·f))^2·(1/d)^n
% Gt: Gain in transmitter antenna [dB]
% Gr: Gain in receiving antenna [dB]
% f: Carrier frequency [Hz]
% d: distance in meter [m]
% n: path loss exponent (Se table below)
%
% Location          n          Standard Deviation
% free space       2.0
% Retail store     2.2          8.7
% Grocery store    1.8          5.7
% Office, hard partitions 3.0          7.0
% Office, soft partitions 2.6          14.1
% Metalworking factory, line of sight 1.6          5,8
% Metalworking factory, obstructed line of sight 3.3          6.8
%
% Constants:
% c = 299.972458e6;          Speed of light in vacuum [m/s]

function out=friis_equation(Gt,Gr,f,n,d);
c = 299.972458e6;          % Speed of light in vacuum [m/s]

out = (Gt + Gr + 20*log10(c/(4*pi*f)) - n*10*log10(d));          % Loss in [dB]
```

4.2 Friis Equation With Ground Reflection

```

% friis_equation_with_ground_presence(h1,h2,d,freq,er,pol)
% This function calculate the loss of a radio link with ground presence
% h1:   Transmitting antenna elevation above ground.
% h2:   Receiving antenna elevation above ground.
% d:    Distance between the two antennas (projected onto ground plane)
% er:   Relative permittivity of ground.
% pol:  Polarization of signal 'H'=horizontal, 'V'=vertical
% freq: Signal frequency in Hz
% Transmitting and receiving antenna assumed ideal isotropic G=0dB
% *****

function retvar=friis_equation_with_ground_presence(h1,h2,d,freq,er,pol)

c=299.972458e6;           % Speed of light in vaccum [m/s]
Gr=1;                   % Antenna Gain receiving antenna.
Gt=1;                   % Antenna Gain transmitting antenna.
Pt=1e-3;                % Energy to the transmitting antenna [Watt]

lambda=c/freq;          % m

phi=atan((h1+h2)./d);    % phi incident angle to ground
direct_wave=sqrt(abs(h1-h2)^2+d.^2); % Distance, traveled direct wave
refl_wave=sqrt(d.^2+(h1+h2)^2); % Distance, traveled reflected wave

if (pol=='H') % horizontal polarization reflection coefficient
    gamma=(sin(phi)-sqrt(er-cos(phi).^2))./(sin(phi)+sqrt(er-cos(phi).^2));
else
    if (pol=='V')% vertical polarization reflection coefficient
        gamma=(er.*sin(phi)-sqrt(er-cos(phi).^2))./(er.*sin(phi)+sqrt(er-cos(phi).^2));
    else
        error([pol, ' is not an valid polarization']);
    end %if
end %if

length_diff=refl_wave-direct_wave;
cos_phase_diff=cos(length_diff.*2*pi/lambda).*sign(gamma);

Direct_energy=Pt*Gt*Gr*lambda^2./((4*pi*direct_wave).^2); reflected_energy=Pt*Gt*Gr*lambda^2./
((4*pi*refl_wave).^2).*abs(gamma);
Total_received_energy=Direct_energy+cos_phase_diff.*reflected_energy;
Total_received_energy_dBm=10*log10(Total_received_energy*1e3); retvar=Total_received_energy_dBm;
%end function

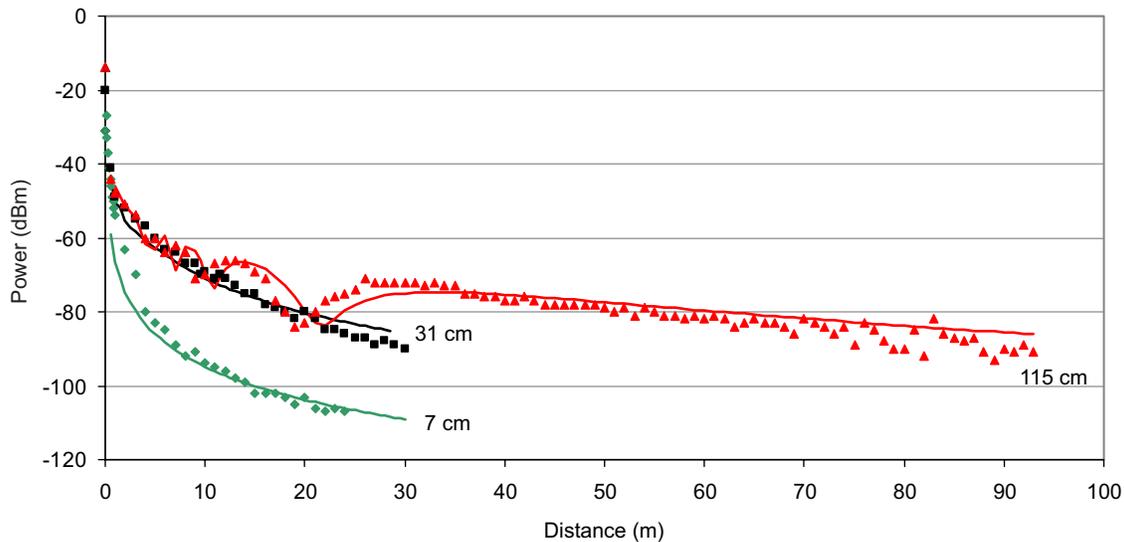
```

4.2.1 Validating the Ground Reflection Model

Figure 4 shows a comparison between the CC2500 operated in a SmartRF04EB and the Matlab ground reflection model. The measurements have been performed on a football field (see Figure 5). Dots are measurements and lines represent calculated values.

A fixed correction level has been added to the calculated values to get an overall better match to the measured values. This correction value represents the difference between the ideal isotropic antenna and the efficiency of the CC2500EMK Evaluation Module and the SmartRF Studio EB. The plotted values are the values measured.

The measured signal energy was higher for the horizontal polarized signal. This is explained by the directivity of a horizontally oriented quarter-wave antenna. When the same antenna is vertically oriented, the energy is radiated in all directions, reducing its effective gain in the direction of the receiver.



NOTE: Signal strengths with transmitter 7 cm, 31 cm, and 115 cm above ground.

Figure 4. Measured and Simulated Signal Strengths

4.2.2 Open Test Field

A rural environment significantly reduces the probability of 2.4-GHz interference. Figure 5 shows the test area where the Matlab ground model was validated.

The EB is mounted on a plastic pole to minimize the influence of the mount on the measurement results.

The iron light towers showed no significant influence on measurements; they were sufficiently far away to allow the direct and ground reflected signals to be the only significant contributors to the total received power.

The presence of a person had significant influence on the measurement. Measurements at each distance were made with nobody present.



Figure 5. Gravel Football Pitch in the Town of Finstadbru

5 Summary

This application report addresses the influence of the ground during range measurements.

It has been shown that multi-path fading can generate confusion during measurements if you are unaware of the phenomenon. Ground presence has also been shown to generate more rapid signal degradation than predicted by Friis equation for free space. Ground reduces the effective range.

Vertical polarization was shown to be less susceptible to ground reflection fading and range degradation than horizontal polarization. For hand held equipment polarization is generally not controllable and this observation has minor importance.

Finally it has been emphasized that other radio traffic influences range measurements and should be controlled or monitored throughout the measurements. For example, make sure that nearby Bluetooth transmitters are off during measurement. Coexistence with other equipment is generally not implemented in test software for range measurements.

6 References

1. *Radar Technology Encyclopedia*, David K. Barton, Sergey A. Leonov, 1997 Artech House Inc. Boston/London, ISBN 0-89006-893-3

Revision History

NOTE: Page numbers for previous revisions may differ from page numbers in the current version.

Changes from April 5, 2008 to June 21, 2018	Page
• Changes to document format and editorial updates throughout document	1

IMPORTANT NOTICE FOR TI DESIGN INFORMATION AND RESOURCES

Texas Instruments Incorporated ("TI") technical, application or other design advice, services or information, including, but not limited to, reference designs and materials relating to evaluation modules, (collectively, "TI Resources") are intended to assist designers who are developing applications that incorporate TI products; by downloading, accessing or using any particular TI Resource in any way, you (individually or, if you are acting on behalf of a company, your company) agree to use it solely for this purpose and subject to the terms of this Notice.

TI's provision of TI Resources does not expand or otherwise alter TI's applicable published warranties or warranty disclaimers for TI products, and no additional obligations or liabilities arise from TI providing such TI Resources. TI reserves the right to make corrections, enhancements, improvements and other changes to its TI Resources.

You understand and agree that you remain responsible for using your independent analysis, evaluation and judgment in designing your applications and that you have full and exclusive responsibility to assure the safety of your applications and compliance of your applications (and of all TI products used in or for your applications) with all applicable regulations, laws and other applicable requirements. You represent that, with respect to your applications, you have all the necessary expertise to create and implement safeguards that (1) anticipate dangerous consequences of failures, (2) monitor failures and their consequences, and (3) lessen the likelihood of failures that might cause harm and take appropriate actions. You agree that prior to using or distributing any applications that include TI products, you will thoroughly test such applications and the functionality of such TI products as used in such applications. TI has not conducted any testing other than that specifically described in the published documentation for a particular TI Resource.

You are authorized to use, copy and modify any individual TI Resource only in connection with the development of applications that include the TI product(s) identified in such TI Resource. NO OTHER LICENSE, EXPRESS OR IMPLIED, BY ESTOPPEL OR OTHERWISE TO ANY OTHER TI INTELLECTUAL PROPERTY RIGHT, AND NO LICENSE TO ANY TECHNOLOGY OR INTELLECTUAL PROPERTY RIGHT OF TI OR ANY THIRD PARTY IS GRANTED HEREIN, including but not limited to any patent right, copyright, mask work right, or other intellectual property right relating to any combination, machine, or process in which TI products or services are used. Information regarding or referencing third-party products or services does not constitute a license to use such products or services, or a warranty or endorsement thereof. Use of TI Resources may require a license from a third party under the patents or other intellectual property of the third party, or a license from TI under the patents or other intellectual property of TI.

TI RESOURCES ARE PROVIDED "AS IS" AND WITH ALL FAULTS. TI DISCLAIMS ALL OTHER WARRANTIES OR REPRESENTATIONS, EXPRESS OR IMPLIED, REGARDING TI RESOURCES OR USE THEREOF, INCLUDING BUT NOT LIMITED TO ACCURACY OR COMPLETENESS, TITLE, ANY EPIDEMIC FAILURE WARRANTY AND ANY IMPLIED WARRANTIES OF MERCHANTABILITY, FITNESS FOR A PARTICULAR PURPOSE, AND NON-INFRINGEMENT OF ANY THIRD PARTY INTELLECTUAL PROPERTY RIGHTS.

TI SHALL NOT BE LIABLE FOR AND SHALL NOT DEFEND OR INDEMNIFY YOU AGAINST ANY CLAIM, INCLUDING BUT NOT LIMITED TO ANY INFRINGEMENT CLAIM THAT RELATES TO OR IS BASED ON ANY COMBINATION OF PRODUCTS EVEN IF DESCRIBED IN TI RESOURCES OR OTHERWISE. IN NO EVENT SHALL TI BE LIABLE FOR ANY ACTUAL, DIRECT, SPECIAL, COLLATERAL, INDIRECT, PUNITIVE, INCIDENTAL, CONSEQUENTIAL OR EXEMPLARY DAMAGES IN CONNECTION WITH OR ARISING OUT OF TI RESOURCES OR USE THEREOF, AND REGARDLESS OF WHETHER TI HAS BEEN ADVISED OF THE POSSIBILITY OF SUCH DAMAGES.

You agree to fully indemnify TI and its representatives against any damages, costs, losses, and/or liabilities arising out of your non-compliance with the terms and provisions of this Notice.

This Notice applies to TI Resources. Additional terms apply to the use and purchase of certain types of materials, TI products and services. These include; without limitation, TI's standard terms for semiconductor products (<http://www.ti.com/sc/docs/stdterms.htm>), [evaluation modules](#), and [samples](http://www.ti.com/sc/docs/sampterm.htm) (<http://www.ti.com/sc/docs/sampterm.htm>).

Mailing Address: Texas Instruments, Post Office Box 655303, Dallas, Texas 75265
Copyright © 2018, Texas Instruments Incorporated