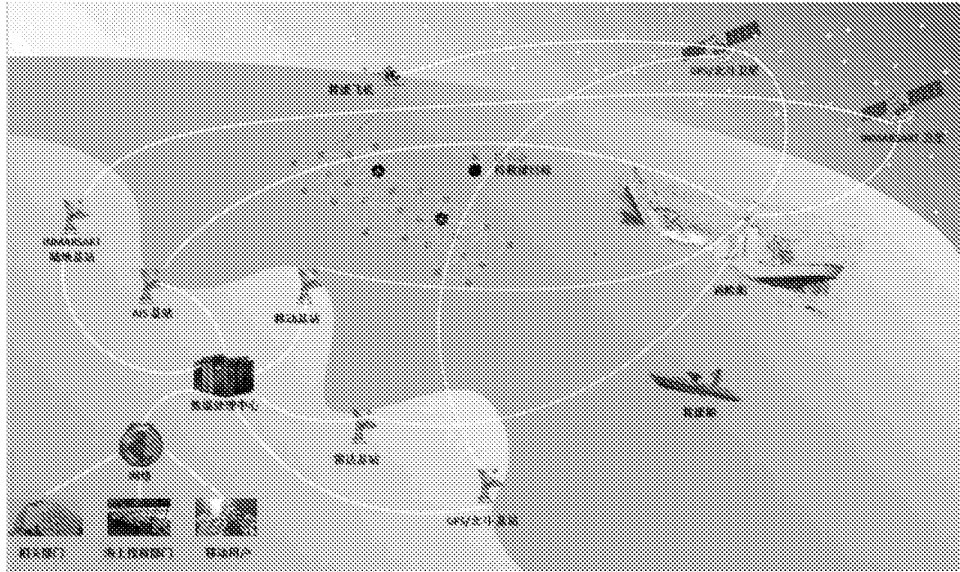
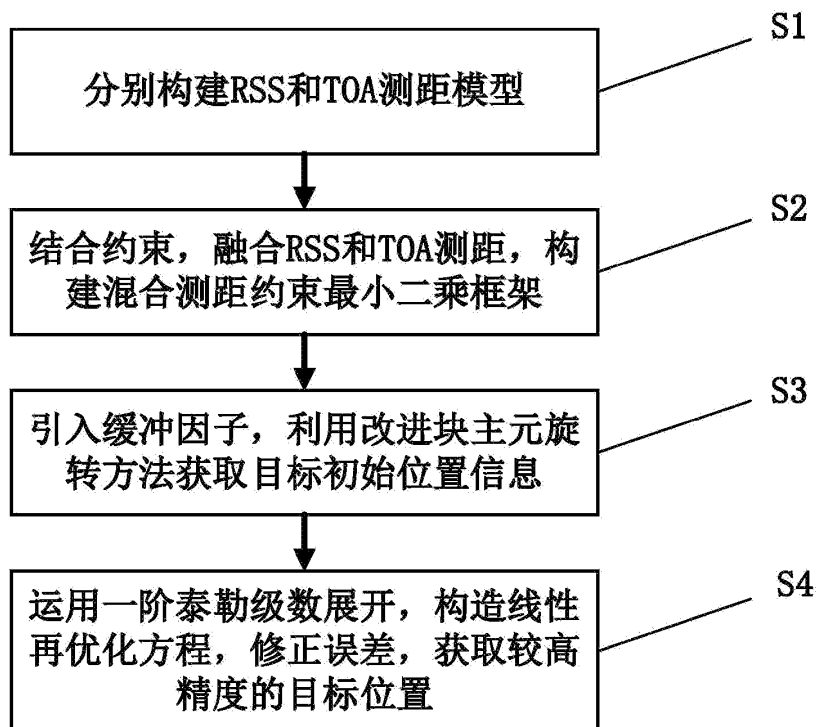


[图 1]



[图 2]

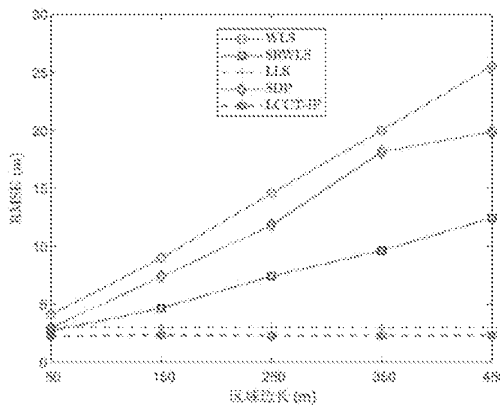


[图 3]

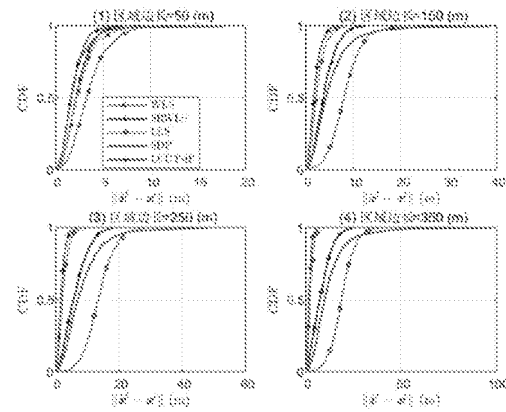
改进块主元旋转定位算法:

1. 初始化: $\kappa = \emptyset$, $\mathcal{G} = \{1, 2, 3\}$, $\xi = 0$, $\Psi = -(A^T)^T B^T$, $\varphi = 3$, $\beta = M + 1$
2. 根据式 (8) 和式 (9) 计算互补基解 $(\xi_\kappa, \Psi_\kappa)$
3. **While** (ξ_κ, Ψ_κ 为非可行解) **do**
4. 根据式 (10) 获取 Γ
5. 若 $|\Gamma| < \beta$, 则 $\beta = |\Gamma|$, $\varphi = 3$, $R = \Gamma$;
6. 若 $|\Gamma| \geq \beta$ 且 $\varphi \geq 1$, 则 $\varphi = \varphi - 1$, $R = \Gamma$;
7. 若 $|\Gamma| \geq \beta$ 且 $\varphi = 1$, 则 R 被定义为式 (12);
8. 根据式 (11) 更新 κ 和 $\mathcal{G}$
9. 根据式 (8) 和式 (9) 更新 ξ_κ 和 Ψ_κ
10. **End While**

[图 4]

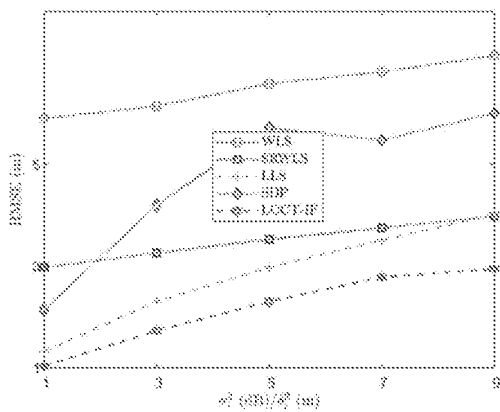


(a) 不同监测区域的定位误差

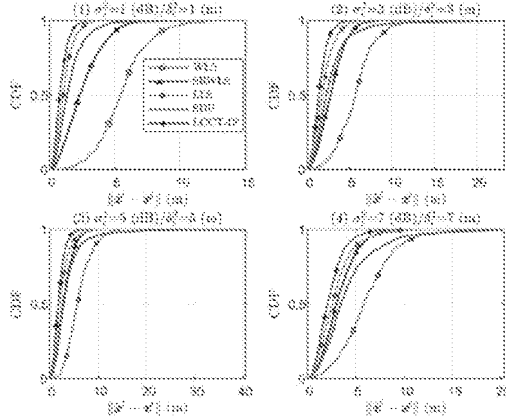


(b) 不同监测区域的 CDF

[图 5]



(a) 不同噪声的定位误差



(b) 不同噪声的 CDF

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