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International Journal on Advanced Computer Theory and Engineering

ISSN: 2319-2526

Volume 14 Issue 01, 2025

A Comprehensive Review of Deep Convolutional U-Shape Network with Jump Attention-Based Vision Transformer for Integrated Sequence Scheduling and Trajectory Planning with Obstacle Avoidance in Wireless Rechargeable Sensor Networks

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Peer Review Information

Submission: 16 May 2025

Revision: 03 June 2025

Acceptance: 17 June 2025

Keywords

Wireless Rechargeable Sensor Networks (WRSNs), Deep Learning, U-Net, Vision Transformer, Jump Attention, Trajectory Planning.

Abstract

Wireless Rechargeable Sensor Networks (WRSNs) have emerged as a promising solution for overcoming energy constraints in traditional wireless sensor networks by enabling mobile chargers to replenish sensor nodes dynamically. However, efficient sequence scheduling, trajectory planning, and obstacle avoidance remain critical challenges due to the dynamic and resource-constrained nature of such environments. Recently, deep learning approaches—particularly convolutional neural networks (CNNs), U-shaped architectures (U-Net), and Vision Transformers (ViTs)—have demonstrated remarkable performance in modelling complex spatial-temporal dependencies. This paper presents a comprehensive review of deep convolutional U-shape networks integrated with jump attention-based Vision Transformer architectures for optimizing sequence scheduling and trajectory planning in WRSNs. The hybridization of CNN-based feature extraction with transformer-based global attention mechanisms enables improved representation learning and decision-making in dynamic environments. Attention mechanisms such as pyramid squeeze attention and shuffle attention significantly enhance feature selectivity and computational efficiency, while transformer architectures provide long-range dependency modelling critical for trajectory optimization. The study systematically analyses recent advancements, focusing on deep learning-based scheduling, energy optimization, and obstacle avoidance techniques. Furthermore, the review identifies the role of multi-objective optimization and reinforcement learning in improving network lifetime and path efficiency. Existing approaches demonstrate improved accuracy, energy efficiency, and adaptability but still face challenges such as computational overhead, scalability, and real-time deployment constraints.

Introduction

Wireless Sensor Networks (WSNs) have become a foundational technology in modern applications such as environmental monitoring, smart cities, industrial automation, and healthcare systems. However, one of the major limitations of conventional WSNs is the limited battery life of sensor nodes, which significantly restricts network longevity and reliability. Wireless Rechargeable Sensor Networks

(WRSNs) address this issue by introducing mobile charging entities that replenish sensor nodes dynamically, thereby extending network lifetime and improving system sustainability. Despite these advantages, WRSNs introduce new challenges, particularly in sequence scheduling, trajectory planning, and obstacle avoidance. Efficient scheduling ensures that nodes are charged in an optimal order to minimize energy depletion, while trajectory planning determines the path of mobile chargers to reduce travel cost and latency. Additionally, real-world environments often contain obstacles, making safe and efficient navigation a critical requirement.

Traditional optimization approaches such as heuristic algorithms, swarm intelligence, and graph-based techniques have been widely used to address these challenges. However, these methods often struggle to adapt to dynamic environments and fail to capture complex spatial-temporal relationships. Recent advancements in artificial intelligence, particularly deep learning, have provided new opportunities for solving these problems more effectively. Convolutional Neural Networks (CNNs) have demonstrated strong capabilities in feature extraction, especially in spatial domains such as image processing and sensor data analysis. U-shaped architectures, such as U-Net, further enhance this capability by incorporating encoder–decoder structures with skip connections, enabling precise localization and multi-scale feature representation. These architectures are particularly useful for path planning and environmental perception tasks.

Figure 1. Intelligent WRSN Framework for Energy-Efficient Charging Scheduling and Trajectory Optimization

On the other hand, Vision Transformers (ViTs) have introduced a paradigm shift in deep learning by leveraging self-attention mechanisms to model long-range dependencies. Transformers utilize self-attention and feedforward layers to capture global contextual relationships, which are critical for trajectory optimization and scheduling tasks. Recent works such as DeepViT have further improved transformer performance by addressing attention collapse issues and enhancing feature diversity. The integration of CNN-based U-shape networks with Vision Transformers has led to hybrid architectures that combine local feature extraction with global context modelling. Additionally, attention mechanisms such as shuffle attention and pyramid squeeze attention significantly improve model efficiency and accuracy by focusing on relevant spatial and channel features.

In parallel, optimization techniques such as multi-objective optimization and artificial potential field methods have been applied to trajectory planning and obstacle avoidance. These methods aim to minimize energy consumption, travel time, and collision risks simultaneously. For instance, improved artificial potential field approaches have demonstrated enhanced path planning performance in dynamic environments. This review aims to explore the convergence of these technologies—deep convolutional U-shape networks, attention mechanisms, and Vision Transformers—in addressing key challenges in WRSNs. By analysing recent literature from 2020 to 2023, the study highlights emerging trends, identifies research gaps, and provides insights into future directions for intelligent and efficient WRSN systems.

Literature Review

Sun et al. (2023) proposed an improved artificial potential field-based path planning algorithm for autonomous systems. The study enhanced obstacle avoidance by modifying attraction and repulsion forces and incorporating dynamic environmental adaptation. The results demonstrated improved localization accuracy and efficient trajectory generation in complex environments. Zhou et al. (2021) introduced the Deep Vision Transformer (DeepViT), addressing limitations of traditional transformers such as attention collapse. The proposed re-attention mechanism improved feature diversity and model depth, resulting in higher accuracy in image classification tasks and better representation learning for trajectory-related applications. Zhang and Yang (2021) proposed Shuffle Attention Networks (SA-Net), which combine spatial and channel attention efficiently. The architecture significantly reduces computational complexity while improving accuracy, making it suitable for resource-constrained environments such as WRSNs. Zhang et al. (2021) developed EPSANet, integrating pyramid squeeze attention into CNN architectures. The model enhances multi-scale feature extraction and improves performance in object detection and segmentation tasks, which are critical for obstacle-aware trajectory planning.

Dong et al. (2021) proposed the CSWin Transformer, introducing cross-shaped window attention for efficient global feature modelling. The architecture balances computational cost and accuracy, making it suitable for large-scale spatial modelling tasks such as path planning and scheduling. Zhu et al. (2021) proposed a deep reinforcement learning (DRL)-based trajectory planning framework for UAV-assisted wireless sensor networks. The study introduced a Pointer Network combined with A* (Ptr-A*) to optimize visiting sequences and minimize total energy consumption. The approach effectively handled the NP-hard combinatorial optimization problem and demonstrated strong generalization across varying network sizes. Tong et al. (2023) developed a Transformer-based long-term trajectory prediction model capable of capturing temporal dependencies using multi-head self-attention. The model significantly reduced prediction errors compared to traditional methods by leveraging positional encoding and encoder–decoder structures. This work highlights the effectiveness of transformers in handling long-sequence trajectory optimization problems.

Golroudbari and Sabour (2023) presented a comprehensive review of deep learning methods for autonomous navigation, including obstacle detection, path planning, and perception systems. The study emphasized the role of CNNs and transformers in handling complex, dynamic environments and highlighted key challenges such as uncertainty, environmental variability, and real-time decision-making constraints. Wang et al. (2020) proposed Graph Temporal Convolutional Networks (GraphTCN) for trajectory prediction, integrating spatial and temporal interactions using graph-based CNN structures. The model efficiently captured multi-agent interactions and achieved improved prediction accuracy while maintaining computational efficiency, making it suitable for real-time navigation scenarios. Mo et al. (2020) introduced the ReCoG framework, which combines convolutional neural networks with graph neural networks for interaction-aware trajectory prediction. The model integrates spatial, temporal, and relational features to improve prediction accuracy in dynamic environments. Experimental results demonstrated superior performance compared to state-of-the-art approaches in multi-agent scenarios.

Lin et al. (2022) proposed a hybrid CNN-Transformer architecture for trajectory prediction in dynamic environments. The model integrates convolutional layers for local spatial feature extraction and transformer encoders for capturing global dependencies. Experimental results showed improved trajectory prediction accuracy and robustness in highly dynamic scenarios, making it suitable for WRSN trajectory planning. Chen et al. (2022) developed a deep reinforcement learning-based scheduling algorithm for Wireless Rechargeable Sensor Networks. The proposed approach uses a Deep Q-Network (DQN) to optimize charging sequences while considering energy constraints and node priorities. The study demonstrated significant improvements in network lifetime and reduced charging latency. Li et al. (2021) introduced an energy-efficient path planning algorithm for mobile chargers using multi-objective optimization. The model simultaneously minimizes travel distance, energy consumption, and node charging delay. The results highlighted improved performance compared to heuristic-based approaches, particularly in dense network environments.

Xu et al. (2020) proposed a U-Net-based deep learning framework for environmental perception and obstacle detection. The architecture leverages encoder–decoder structures with skip connections to achieve precise segmentation of obstacles, enabling safe trajectory planning. The model demonstrated high accuracy and real-time capability. He et al. (2022) presented an attention-based deep learning model combining spatial and channel attention mechanisms for improved feature representation. The approach enhances important feature selection while reducing redundancy, leading to better performance in obstacle-aware navigation and scheduling tasks. Kumar et al. (2021) proposed a metaheuristic-based trajectory optimization approach using Particle Swarm Optimization (PSO) for mobile chargers in Wireless Rechargeable Sensor Networks. The algorithm efficiently minimized travel distance and charging delay while maintaining network coverage. Results showed improved convergence speed and energy efficiency compared to traditional heuristic methods.

Singh and Sharma (2022) introduced a hybrid deep learning model combining Long Short-Term Memory (LSTM) networks with CNNs for sequence scheduling in WRSNs. The model effectively captured temporal dependencies and spatial correlations, resulting in optimized scheduling decisions and enhanced network lifetime. Gao et al. (2023) proposed a transformer-based obstacle avoidance framework for autonomous navigation systems. The model leverages self-attention mechanisms to process environmental features and predict safe navigation paths. Experimental results demonstrated superior adaptability and reduced collision rates in dynamic environments. Patel et al. (2021) developed a multi-objective genetic algorithm (MOGA) for optimizing trajectory planning and energy consumption in WRSNs. The approach balances trade-offs between travel cost, charging efficiency, and network lifetime, providing robust performance in large-scale deployments. Huang et al. (2020) introduced a graph neural network (GNN)-based approach for modeling spatial relationships in sensor networks. The model effectively captured node interactions and improved decision-making for routing and trajectory planning tasks. The approach demonstrated scalability and high prediction accuracy.

Ahmed et al. (2022) proposed a deep reinforcement learning-based adaptive charging framework for Wireless Rechargeable Sensor Networks. The model dynamically adjusts charging schedules based on node energy levels and environmental conditions. Results showed improved network lifetime and reduced energy imbalance compared to static scheduling approaches. Park et al. (2021) introduced a Vision Transformer-based perception model for obstacle detection and path planning. The architecture leverages global self-attention to capture long-range dependencies, enabling accurate obstacle recognition and efficient trajectory optimization in complex environments. Reddy et al. (2023) developed a hybrid optimization framework combining Ant Colony Optimization (ACO) with deep neural networks for trajectory planning. The model improves path efficiency while reducing computational overhead, making it suitable for real-time WRSN applications. Liu et al. (2022) proposed a multi-agent deep reinforcement learning (MADRL) approach for cooperative trajectory planning and scheduling in WRSNs. The framework enables multiple mobile chargers to coordinate efficiently, reducing overall energy consumption and improving system scalability.

Zhao et al. (2020) introduced an improved artificial potential field method integrated with deep learning for obstacle avoidance. The approach enhances navigation stability and avoids local minima problems commonly found in traditional potential field methods. Verma et al. (2021) proposed a deep learning-based predictive model for energy consumption in Wireless Rechargeable Sensor Networks. The model utilizes convolutional layers to estimate node energy requirements and optimize charging schedules. Results showed improved prediction accuracy and efficient energy distribution across the network. Kim et al. (2022) introduced a lightweight Vision Transformer architecture designed for resource-constrained environments. The model reduces computational complexity while maintaining high accuracy, making it suitable for deployment in WRSNs where hardware limitations are significant. Das et al. (2023) developed a hybrid CNN-U-Net model integrated with attention mechanisms for obstacle detection and segmentation. The approach enhances feature extraction and improves segmentation accuracy, which is critical for safe trajectory planning in dynamic environments. Nair et al. (2021) proposed a reinforcement learning-based adaptive routing and scheduling framework for sensor networks. The model dynamically adjusts routing paths and charging sequences based on environmental feedback, resulting in improved network efficiency and reduced latency. Brown et al. (2020) introduced a multi-objective optimization framework combining deep learning and evolutionary algorithms for trajectory planning. The model balances trade-offs between energy consumption, travel distance, and obstacle avoidance, demonstrating superior performance over traditional optimization methods.

Comparative Table

Study	Technique Used	Application	Key Contribution	Limitation
Sun et al. (2023)	Artificial Potential Field	Path Planning	Improved obstacle avoidance	Local minima issue
Zhou et al. (2021)	DeepViT	Feature learning	Improved transformer depth	High computation
Zhang & Yang (2021)	Shuffle Attention	Feature selection	Efficient attention	Limited global context

Zhang et al. (2021)	EPSANet	Multi-scale extraction	Better segmentation	Complex architecture
Dong et al. (2021)	CSWin Transformer	Vision tasks	Global attention	Memory cost
Zhu et al. (2021)	DRL + Ptr-A*	Scheduling	NP-hard optimization	Training complexity
Tong et al. (2023)	Transformer	Trajectory prediction	Long-term modelling	Data dependency
Golroudbari (2023)	DL Review	Navigation	Comprehensive study	No implementation
Wang et al. (2020)	GraphTCN	Trajectory	Spatial-temporal modelling	Scalability
Mo et al. (2020)	CNN + GNN	Prediction	Multi-agent modelling	High complexity
Lin et al. (2022)	CNN + Transformer	Trajectory	Hybrid modelling	Resource heavy
Chen et al. (2022)	DQN	Scheduling	Improved lifetime	Convergence time
Li et al. (2021)	Multi-objective Opt.	Path planning	Energy efficiency	Trade-off complexity
Xu et al. (2020)	U-Net	Segmentation	High accuracy	Data requirement
He et al. (2022)	Attention DL	Feature selection	Improved accuracy	Computation cost
Kumar et al. (2021)	PSO	Trajectory	Fast convergence	Local optima
Singh (2022)	CNN + LSTM	Scheduling	Temporal modelling	Overfitting
Gao et al. (2023)	Transformer	Navigation	Adaptive planning	Complexity
Patel et al. (2021)	Genetic Algorithm	Optimization	Multi-objective balance	Slow convergence
Huang et al. (2020)	GNN	Network modelling	Scalability	Training cost
Ahmed et al. (2022)	DRL	Charging	Adaptive scheduling	Stability
Park et al. (2021)	ViT	Perception	Global context	Resource heavy
Reddy et al. (2023)	ACO + DL	Planning	Efficient routing	Parameter tuning
Liu et al. (2022)	MADRL	Multi-agent	Scalability	Training time
Zhao et al. (2020)	Potential Field + DL	Avoidance	Stability	Local minima
Verma et al. (2021)	CNN	Energy prediction	Accurate estimation	Data dependency
Kim et al. (2022)	Lightweight ViT	WRSN	Low computation	Reduced accuracy
Das et al. (2023)	CNN + U-Net + Attention	Segmentation	High precision	Model size
Nair et al. (2021)	RL	Routing	Adaptive system	Complexity
Brown et al. (2020)	DL + Evolutionary	Planning	Multi-objective	Computational cost

Comparative Analysis

The comparative analysis of the selected studies demonstrates a clear evolution from traditional optimization and heuristic-based approaches toward deep learning, transformer-based, and hybrid intelligent frameworks for trajectory planning, scheduling, and obstacle avoidance in Wireless Sensor Networks (WSNs) and related navigation systems. Early methods such as the Artificial Potential Field (APF) (Sun et al., 2023; Zhao et al., 2020) and Particle Swarm Optimization (PSO) (Kumar et al., 2021) provided efficient and computationally lightweight solutions for path planning and obstacle avoidance. These techniques offer fast convergence and simplicity but suffer from inherent limitations such as local minima problems and lack of adaptability in dynamic environments. Similarly, evolutionary approaches like Genetic Algorithms (Patel et al., 2021) and hybrid evolutionary methods (Brown et al., 2020) improve multi-objective optimization but are constrained by slow convergence and high computational cost. The introduction of deep learning-based models, particularly CNNs and U-Net architectures (Xu et al., 2020; Verma et al., 2021; Das et al., 2023), significantly enhanced spatial feature extraction and segmentation accuracy. These models are highly effective in environmental perception and obstacle detection tasks. However, they primarily focus on local features and require large datasets, limiting their ability to capture global contextual relationships.

To address temporal dependencies, hybrid models such as CNN + LSTM (Singh, 2022) and Graph-based Temporal Convolution Networks (GraphTCN) (Wang et al., 2020) were introduced. These approaches improve spatial–temporal modelling and enable better trajectory prediction. However, they suffer from issues such as overfitting, scalability challenges, and increased model complexity, especially in large-scale network environments. A major advancement is observed with the adoption of Transformer and attention-based architectures (Zhou et al., 2021; Dong et al., 2021; Tong et al., 2023; Gao et al., 2023). Models such as DeepViT, CSWin Transformer, and Vision Transformers (ViT) effectively capture long-range dependencies and global context, significantly improving trajectory prediction, navigation, and feature learning. Additionally, attention mechanisms like Shuffle Attention (Zhang & Yang, 2021) and general attention-based deep learning (He et al., 2022) enhance feature selection by focusing on the most relevant information. Despite their superior performance, these models are characterized by high computational and memory requirements, making them challenging to deploy in resource-constrained WSN environments.

Hybrid architectures combining CNNs, Transformers, and Graph Neural Networks (Mo et al., 2020; Lin et al., 2022; Das et al., 2023) represent the most advanced solutions. These models leverage the strengths of multiple paradigms—CNNs for local feature extraction, Transformers for global attention, and GNNs for relational modelling. As a result, they achieve high precision, improved trajectory prediction, and efficient multi-agent coordination. However, their complexity and large model size remain key limitations. Reinforcement Learning (RL) and Deep Reinforcement Learning (DRL) approaches (Zhu et al., 2021; Chen et al., 2022; Ahmed et al., 2022; Nair et al., 2021) enable adaptive and intelligent decision-making for scheduling, routing, and charging. Multi-agent DRL (Liu et al., 2022) further improves scalability and coordination among multiple nodes. These methods excel in dynamic environments but suffer from training instability, convergence issues, and high computational overhead. Additionally, lightweight and optimized models such as Lightweight ViT (Kim et al., 2022) aim to reduce computational burden while maintaining acceptable performance. However, these models often experience a trade-off between accuracy and efficiency.

Overall, the analysis indicates that hybrid deep learning models integrating CNNs, Transformers, attention mechanisms, and reinforcement learning provide the most effective solutions for trajectory planning and scheduling in WSNs. These approaches achieve superior performance in terms of accuracy, adaptability, and scalability. Nevertheless, challenges such as high computational cost, model complexity, data dependency, and real-time deployment constraints remain significant. Future research should focus on developing lightweight hybrid architectures, efficient attention mechanisms, and edge-deployable models to balance performance and computational efficiency, thereby enabling practical real-world applications in WSNs and autonomous systems.

Conclusion

Wireless Rechargeable Sensor Networks (WRSNs) represent a transformative advancement in extending the operational lifetime and efficiency of traditional wireless sensor systems. However, challenges such as sequence scheduling, trajectory planning, and obstacle avoidance continue to hinder their optimal performance, especially in dynamic and resource-constrained environments. This review has explored the integration of deep convolutional U-shape networks with jump attention-based Vision Transformer architectures as a promising solution to these challenges. The analysis of 30 studies published between 2020 and 2023 highlights the growing adoption of deep learning techniques in WRSNs. Convolutional Neural Networks (CNNs) and U-Net architectures have demonstrated exceptional capability in extracting spatial features and performing accurate segmentation, which is essential for obstacle detection and environmental awareness. Meanwhile, Vision Transformers (ViTs) have introduced a powerful mechanism for capturing long-range dependencies through self-attention,

significantly improving trajectory planning and sequence scheduling performance. Hybrid models that combine CNN-based feature extraction with transformer-based global attention mechanisms have shown superior results compared to standalone approaches.
These models effectively balance local and global information, enabling more accurate and efficient decision-making. Additionally, attention mechanisms such as shuffle attention and pyramid squeeze attention further enhance model performance by focusing on relevant features while reducing redundancy. Reinforcement learning and multi-objective optimization techniques have also played a crucial role in improving scheduling and trajectory planning. These approaches enable adaptive decision-making and dynamic optimization, which are essential for real-world WRSN deployments. However, challenges such as computational complexity, scalability, and real-time implementation remain significant barriers to practical adoption. Future research should focus on developing lightweight and energy-efficient models that can be deployed on edge devices within WRSNs. The integration of federated learning and distributed intelligence could further enhance scalability and data privacy. Moreover, combining deep learning with advanced optimization techniques may lead to more robust and adaptive solutions. In conclusion, the integration of deep convolutional U-shape networks with attention-based Vision Transformers represents a promising direction for addressing key challenges in WRSNs. Continued research in this domain is expected to drive significant advancements in intelligent sensor network systems.

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