ANALYZIS OF EGNOS IONOSPHERIC MODEL

INTRODUCTION

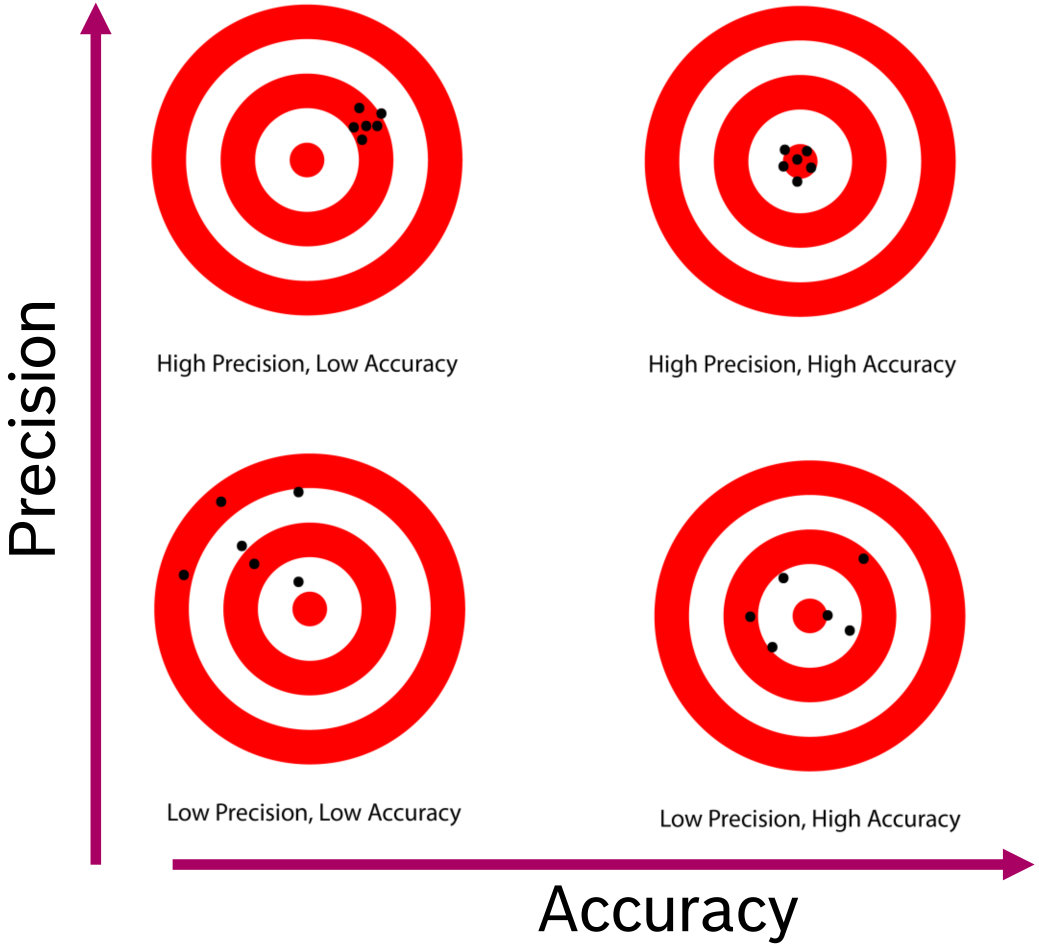
Introduction to Integrity

Integrity – the aim of the EGNOS analyzis

„Integrity is the measure of the trust that can be placed in the correctness of the information supplied by a navigation system. Integrity includes the ability of the system to provide timely warnings to users when the system should not be used for navigation”
- *This definition was adapted from the 2008 US Federal Navigation Plan - Navipedia*

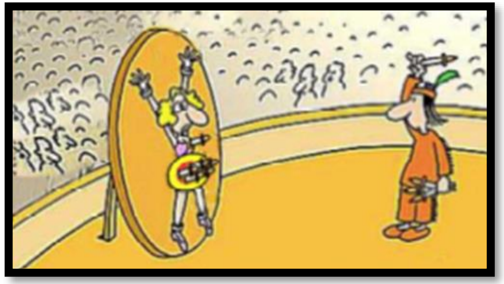
Introduction
Definition of performace key parameter

Accuracy: Measure of navigation output ***deviating from truth***.
Integrity: Ability of a system to ***provide timely warnings*** when the system should not be used for navigation. Integrity risk is the probability of an undetected, threatening navigation system problem.
Availability: Fraction of time navigation system is ***usable as determined by compliance with accuracy, integrity and continuity requirements***.
Continuity: Likelihood that the navigation ***supports accuracy and integrity requirements for the duration of intended operation***. Continuity risk is the probability of a detected but unscheduled navigation interruption after initiation of an operation.



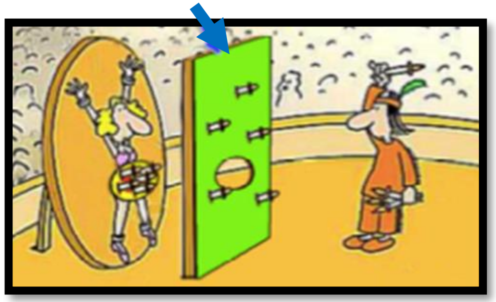
Introduction
System performance

- System performance:
  Accuracy, **Integrity**, **Availability**, **Continuity**

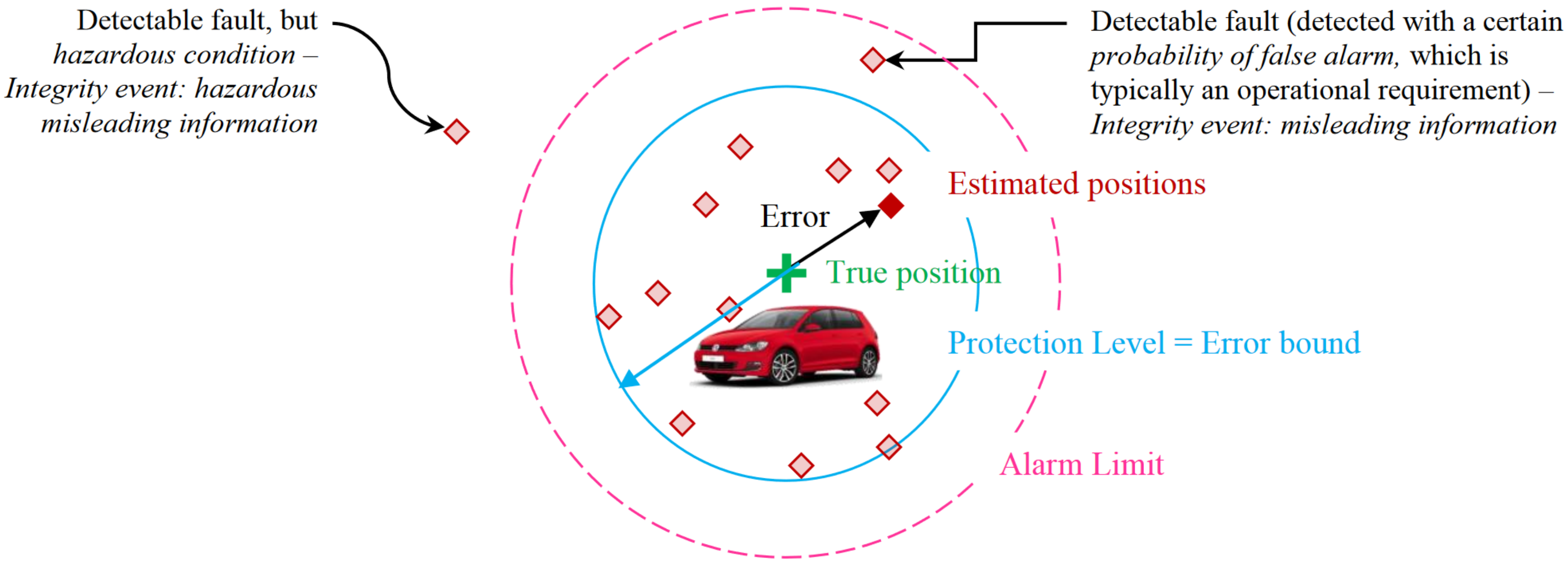


High accuracy, poor integrity

Integrity monitoring/mechanisms



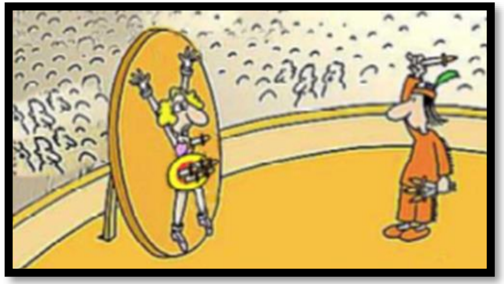
Poor accuracy, high integrity



The concepts of Protection Level, Alarm Limit and integrity events.

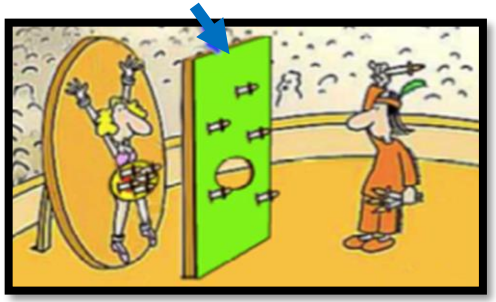
Introduction
Stanford diagram

- System performance:
  Accuracy, **Integrity**, **Availability**, **Continuity**

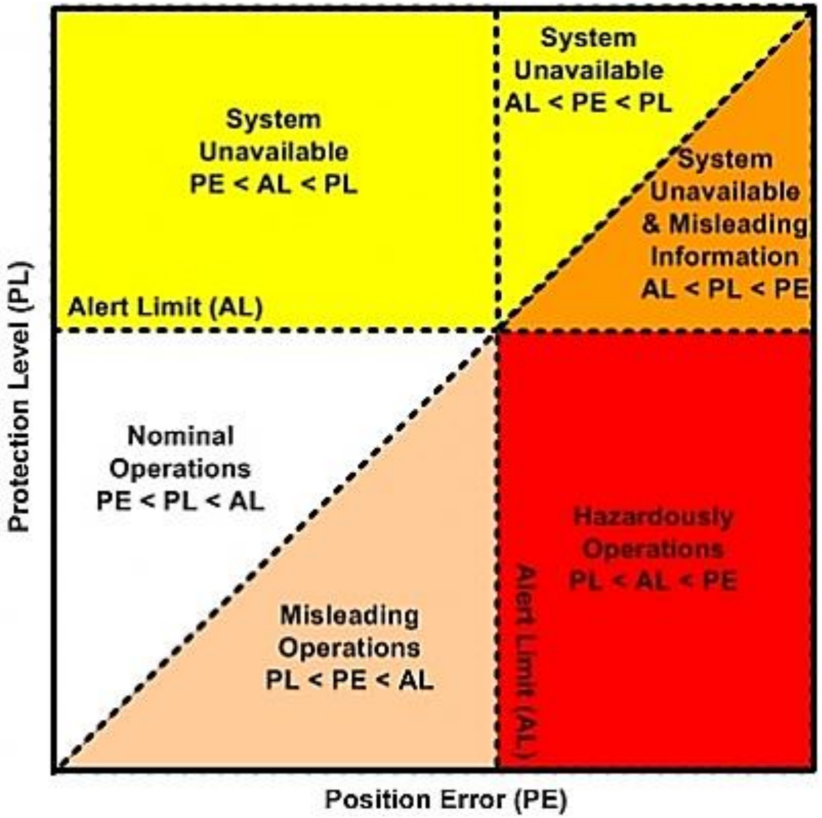


High accuracy, poor integrity

Integrity monitoring/mechanisms



Poor accuracy, high integrity



AL: Alert Limit

PL: Protection Level

PE: Position Estimation

HMI: Hazardously Misleading Information

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EGNOS & GINA

EGNOS
RTCA’s protection level calculation

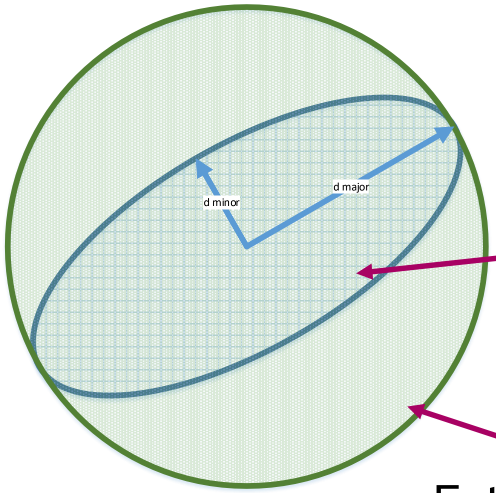
Horizontal protection level

$$HPL = K_H d_{major}$$

$$K_H = 6.0 \; - position\ probability\ 10^{-7}$$

Variance of the residual after application of ionospehric error

$$\sigma_i^2 = \sigma_{i,flt}^2 + \sigma_{i,UIRE}^2 + \sigma_{i,air}^2 + \sigma_{i,tropo}^2$$



Ellipsoid of projection matrix

Estimation of protection level

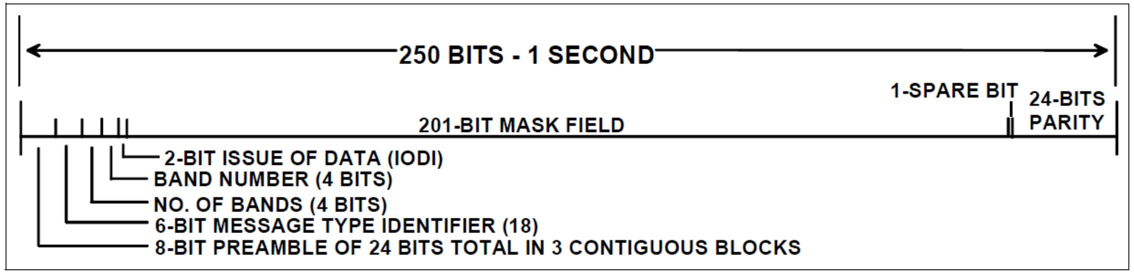
Inverse cummulative function of 2D Gaussian

$$r = F^{-1}(p) = \sqrt{-2\ln(1-p)}$$

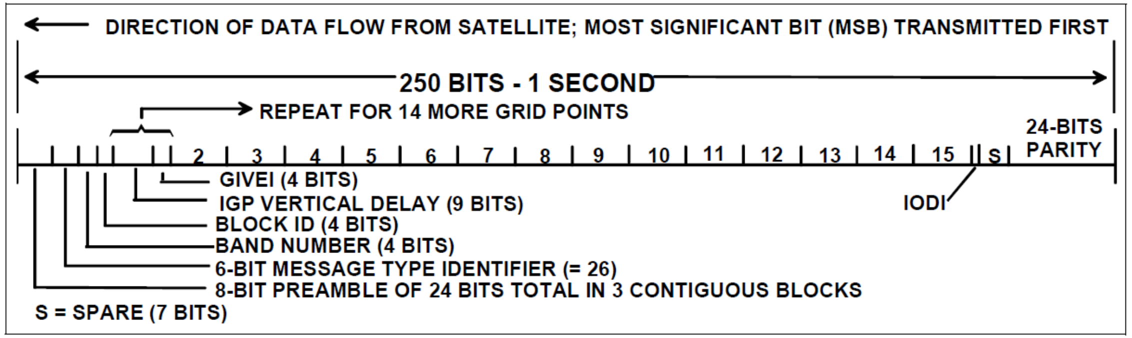
EGNOS

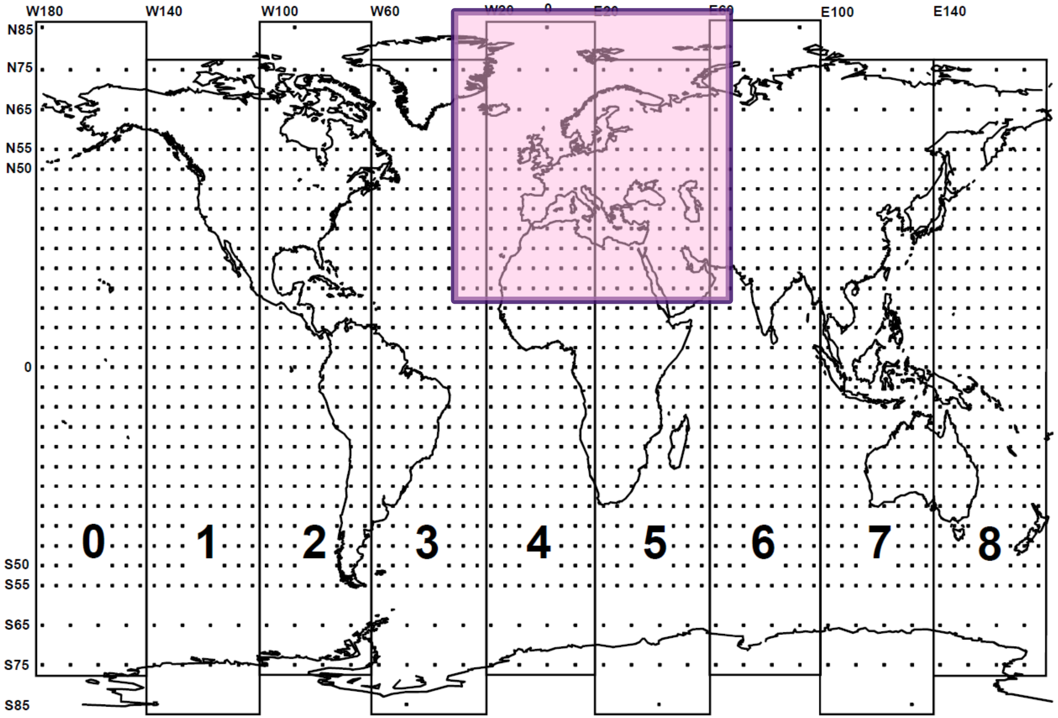
Ionospheric Grid Point and Message Formats

IGP Mask Message Format



Ionospheric Delay Corrections Message Format

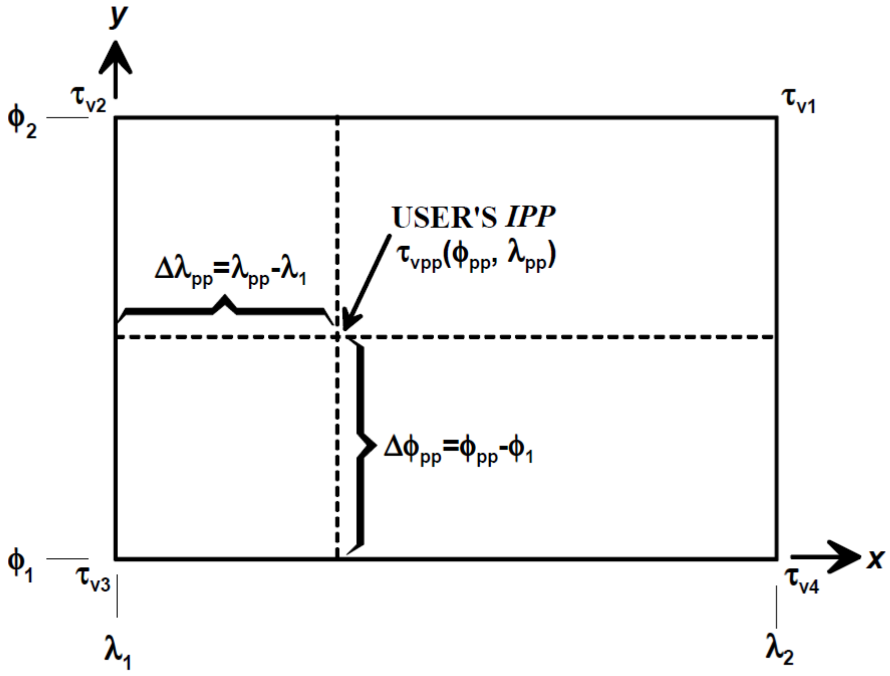


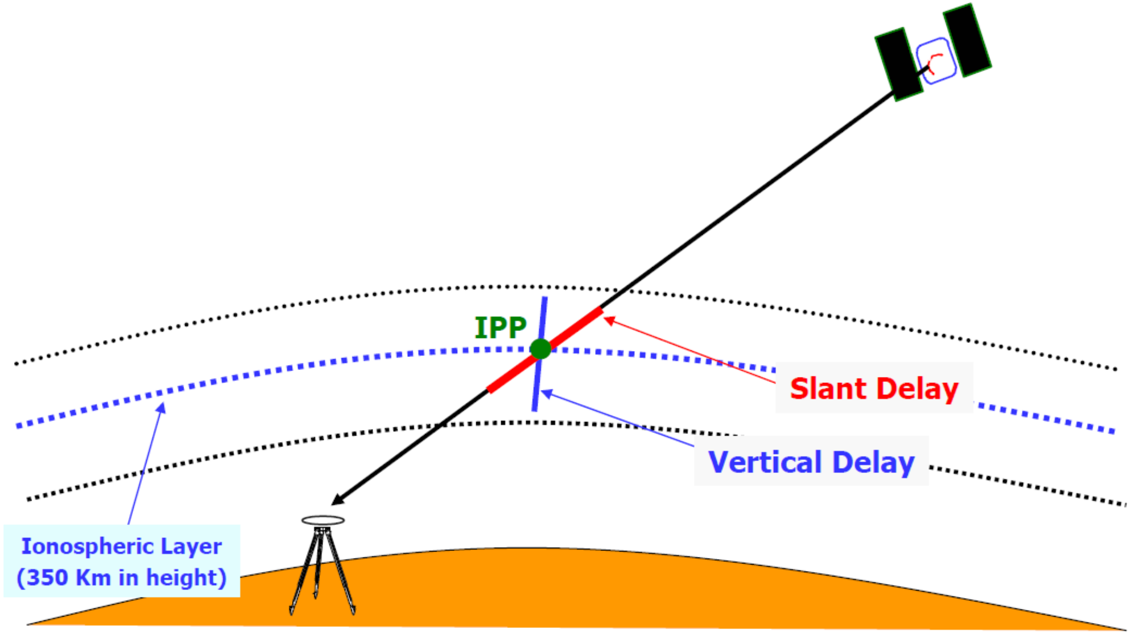


EGNOS
Ionospheric Variance

IONOSPHERIC PIERCE POINTS (IPP)

4 point interpolation algorithm definition





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GINA – Global Integrated Navigation Algorithm
EGNOS

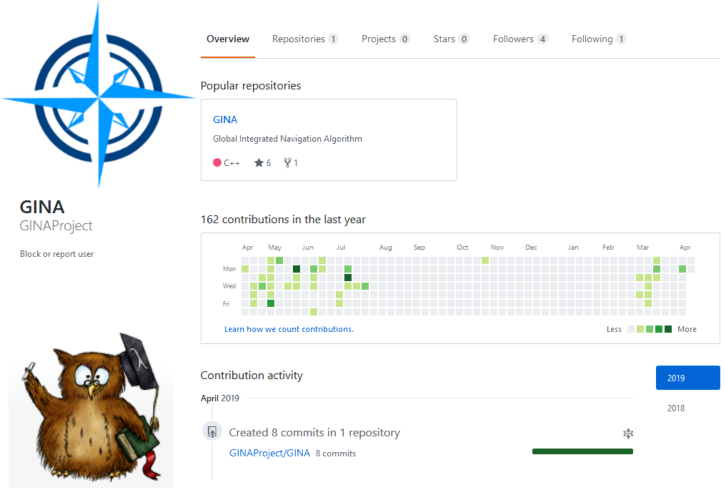
Cmake based C++ project

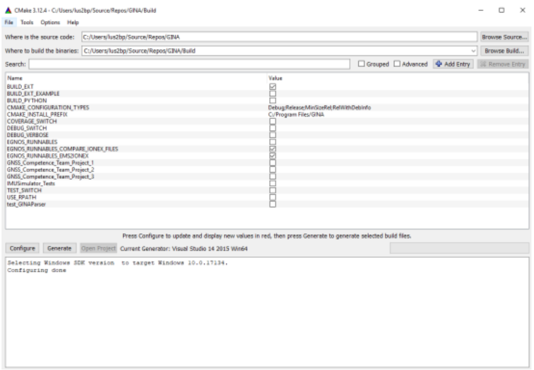
Github Repo

Evaulation with Octova/Matlab

EGNOS is the latest module in GINA

It contains ~5000 Line of Code

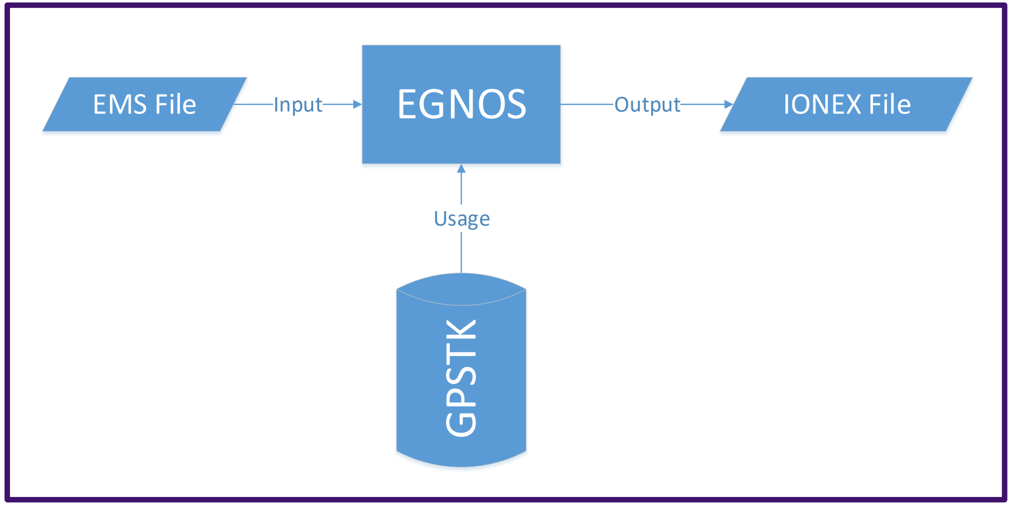




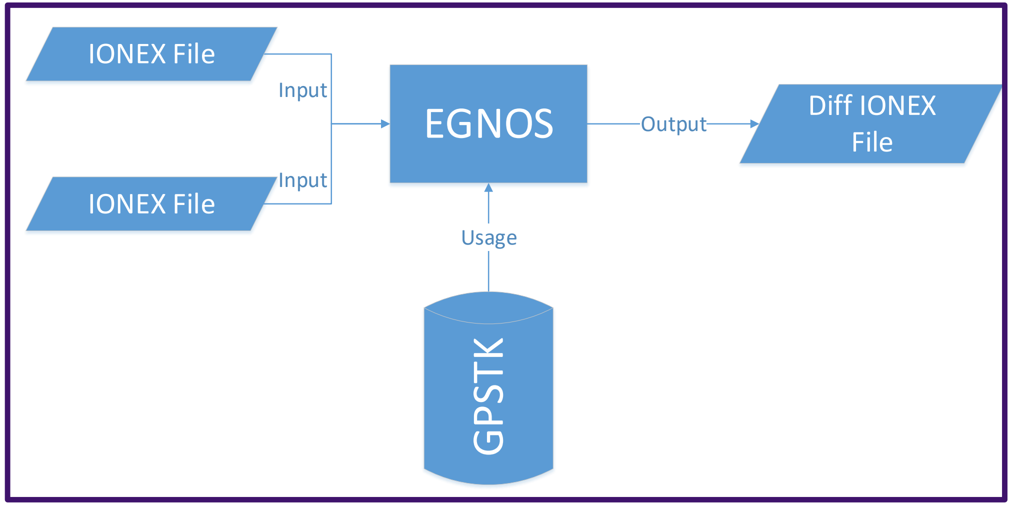
EGNOS - GINA

EGNOS Features – EMS Processing

Create IONEX file from EMS



Difference of IONEX files



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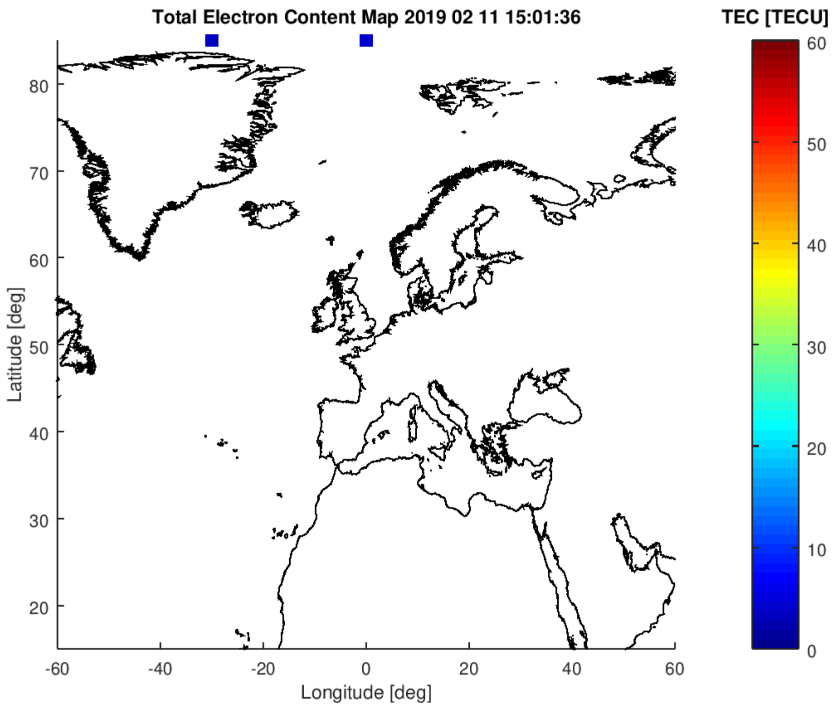
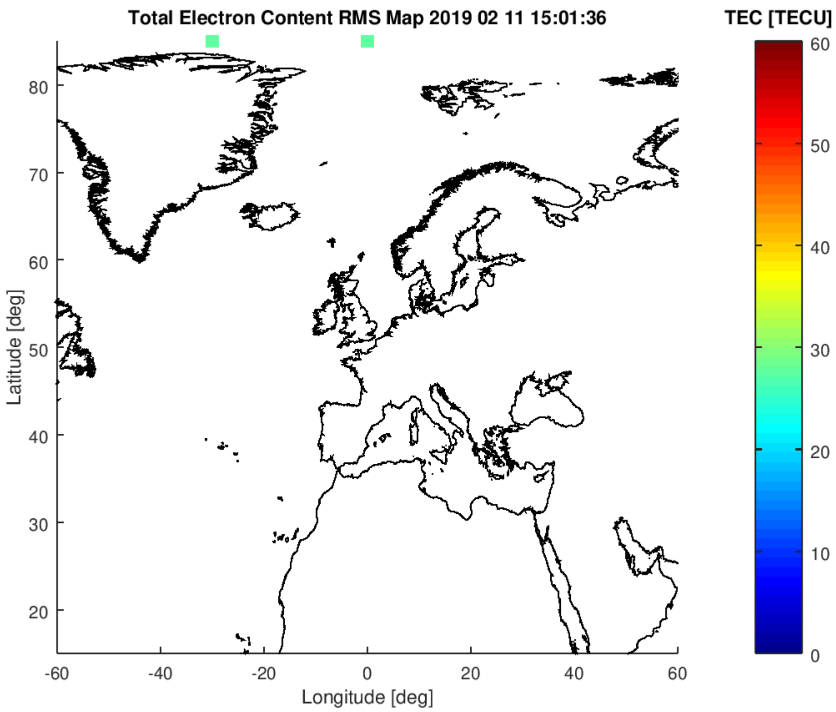
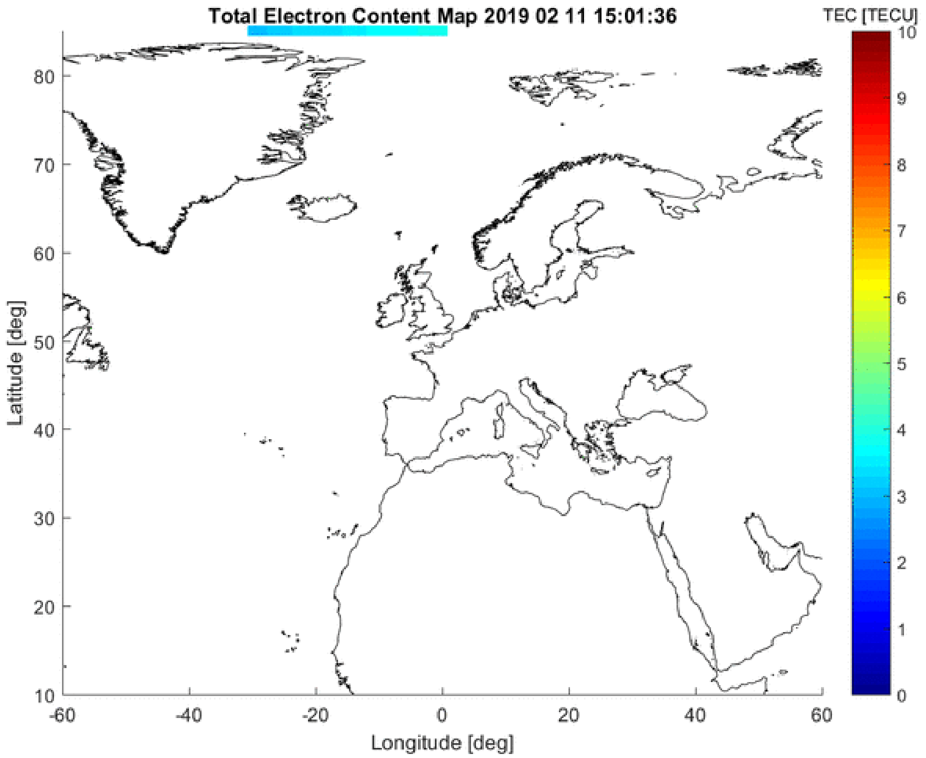
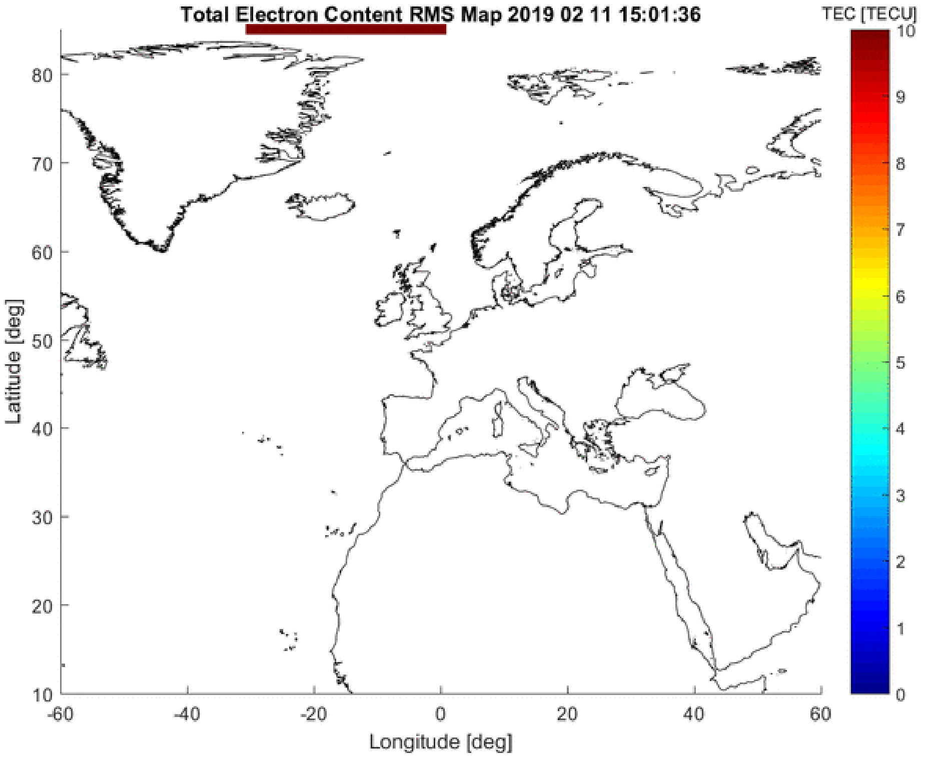
EGNOS - GINA
Raw measurement





EGNOS - GINA
Interpolated IGPs

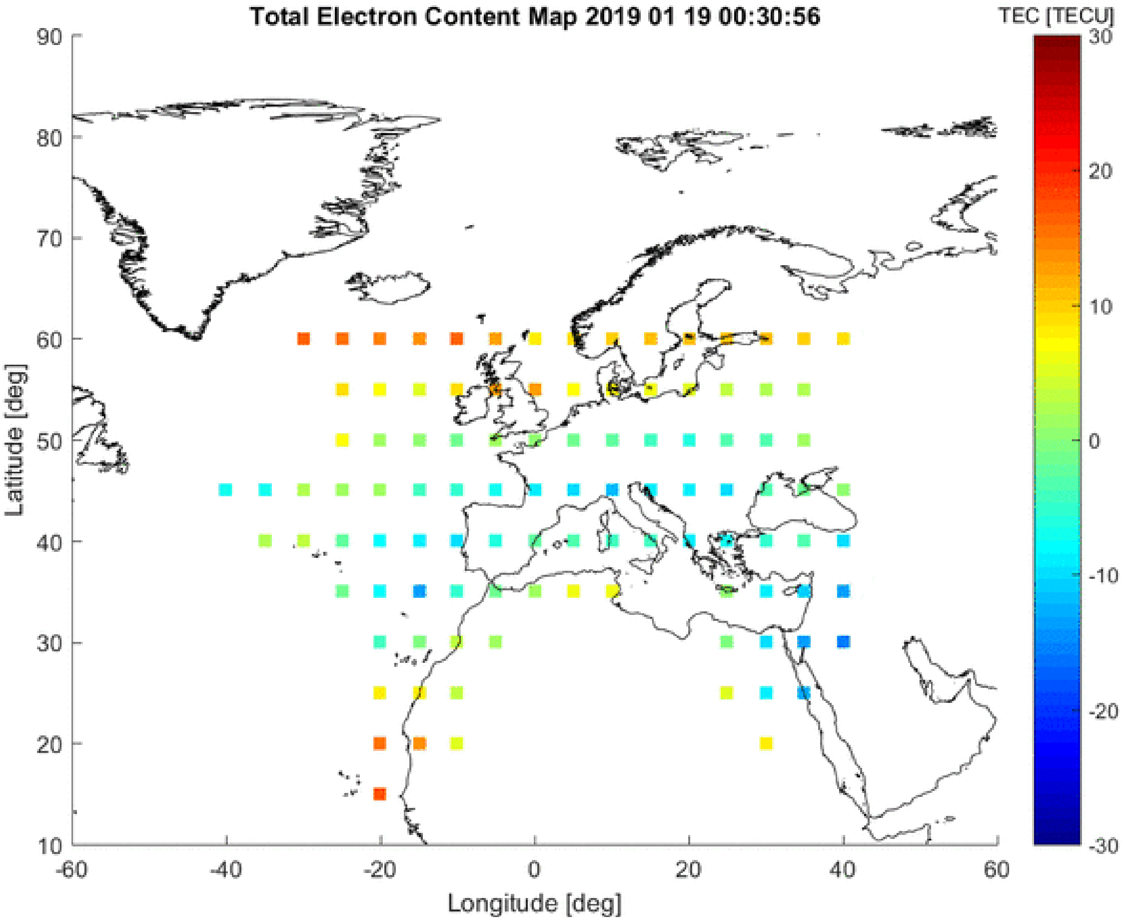




EGNOS - GINA
EMS – CODE's GIM

$$dTEC = TEC_1 - TEC_2$$

$$dRMS = \sqrt{RMS_1^2 + RMS_2^2}$$



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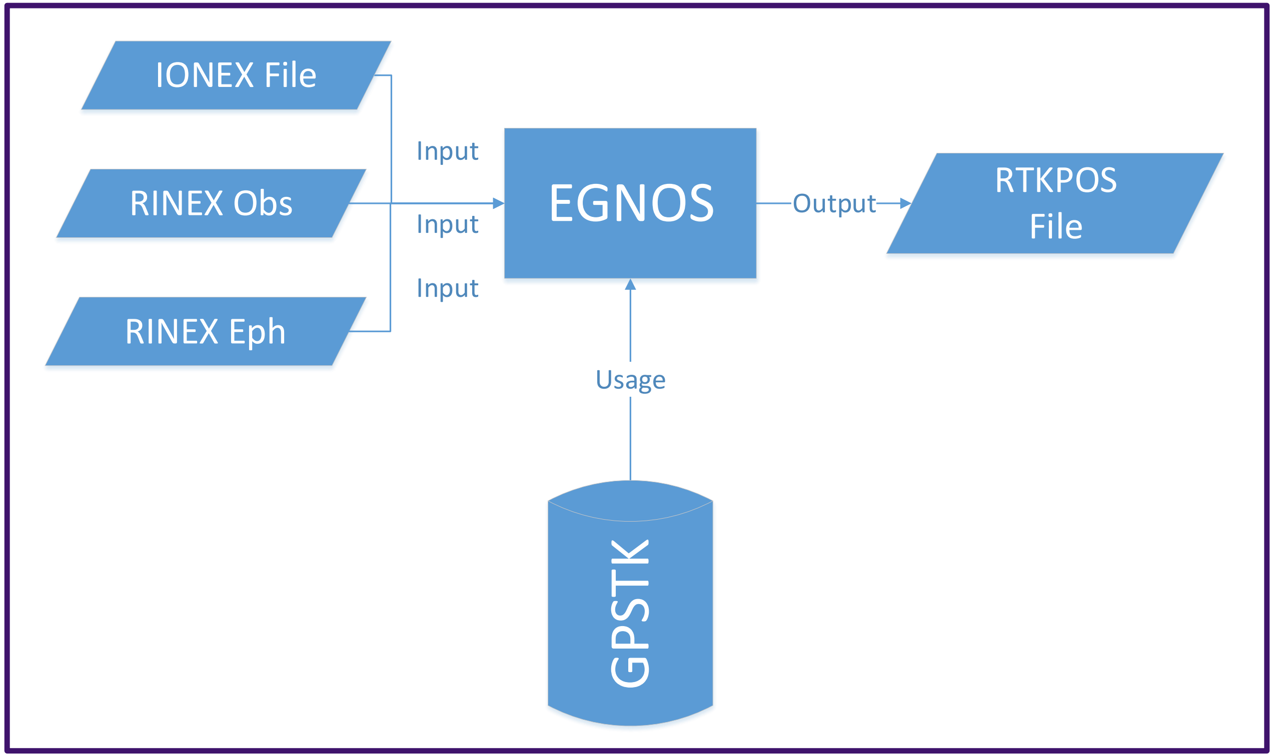
EGNOS - GINA

EGNOS Features – Navigation Engine with EGNOS Iono Model

Calculate position with IONEX correction



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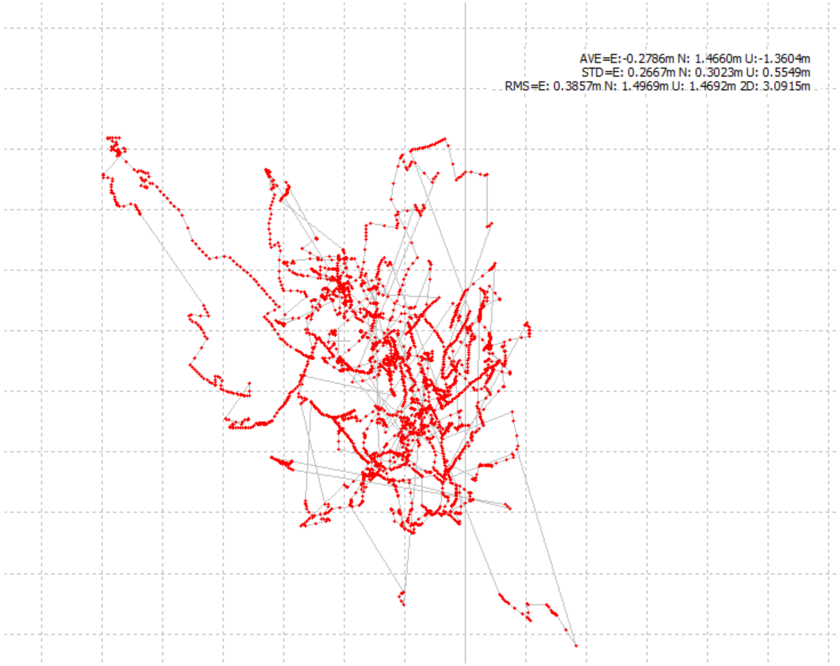
EGNOS - GINA

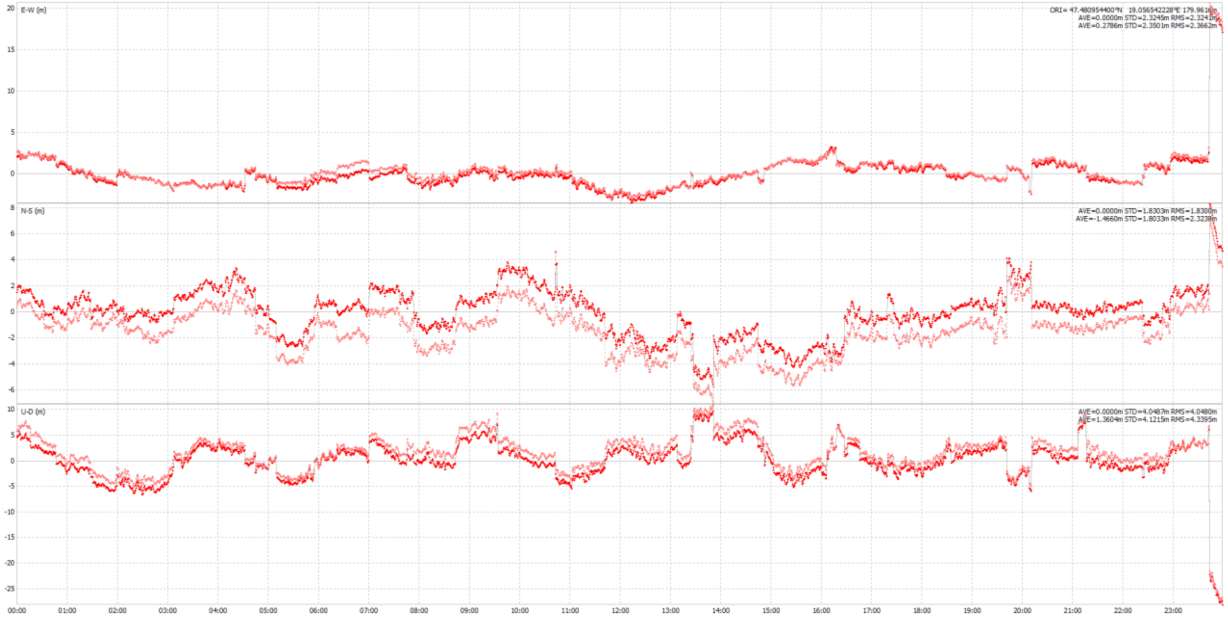
Navigation Engine with EGNOS Iono Model

Position Difference Ground Track

EMS-CODE



Position with EMS and with CODE



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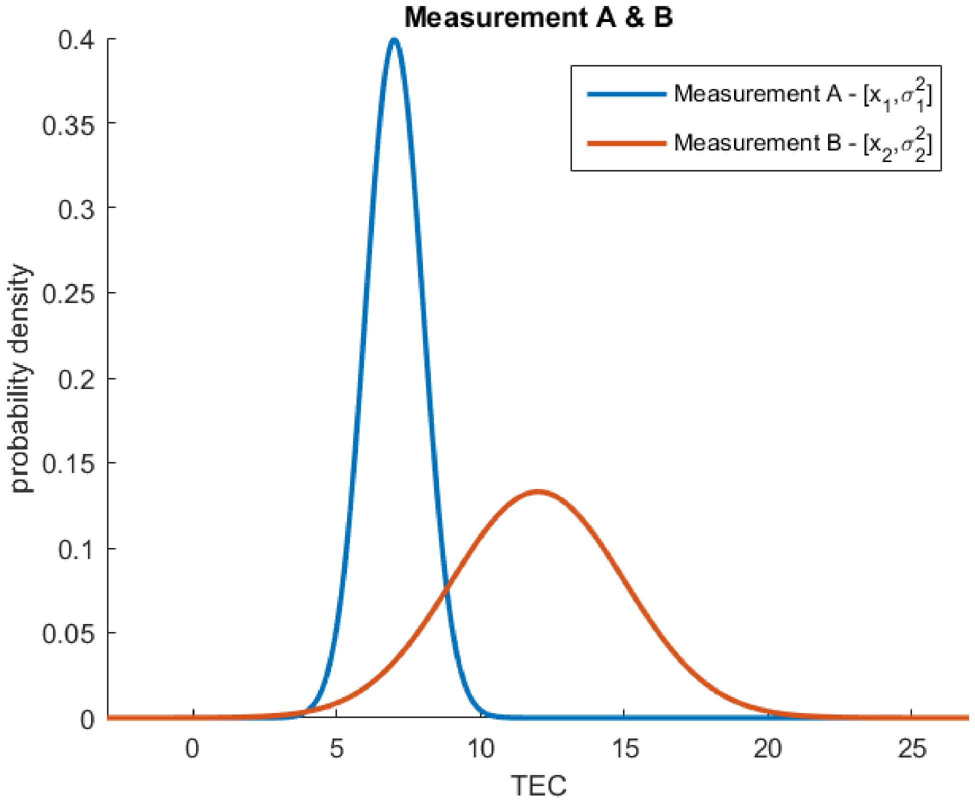
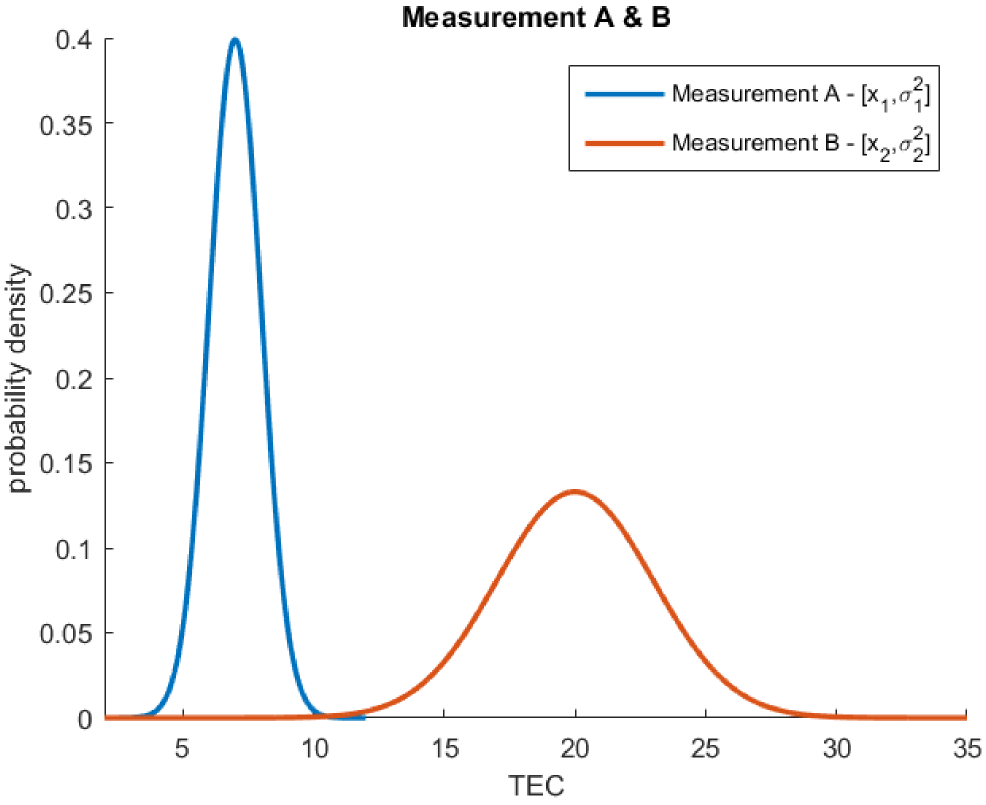
BAYESIAN APPROACH

Bayesian statistic
Are the measurements consistent?





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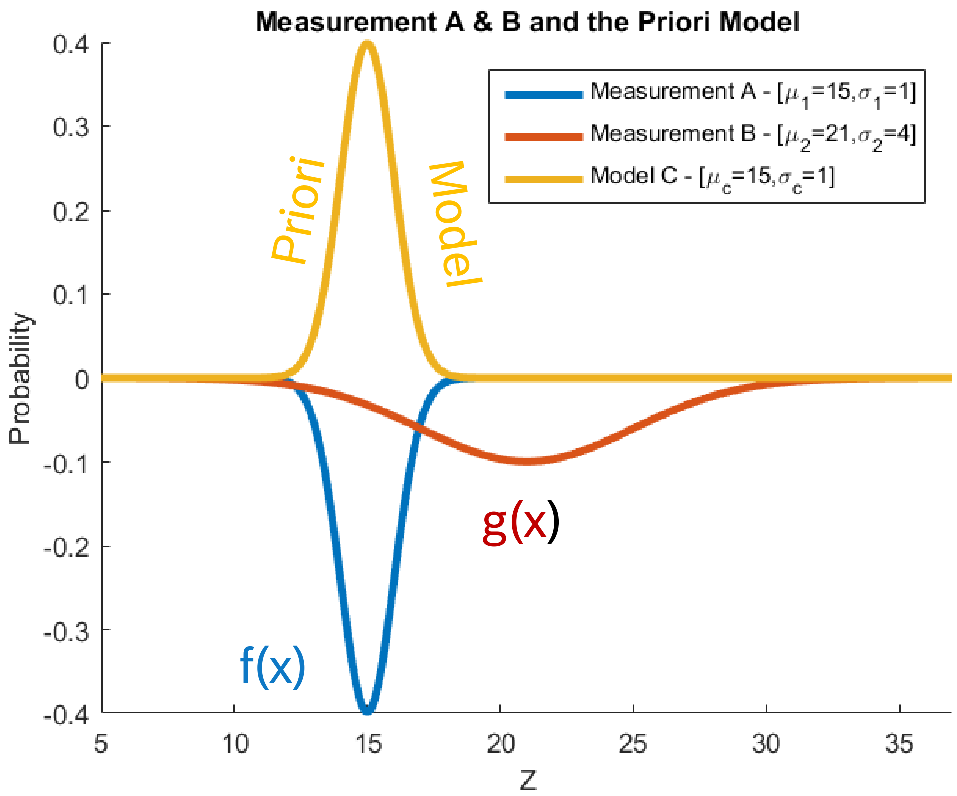
Likelihood of the measurements
Priori beleif is the Measurement A

$$P(A = x_1 \; and \; B = \; x_2 | Priori \; is \; model \; C) = ?$$

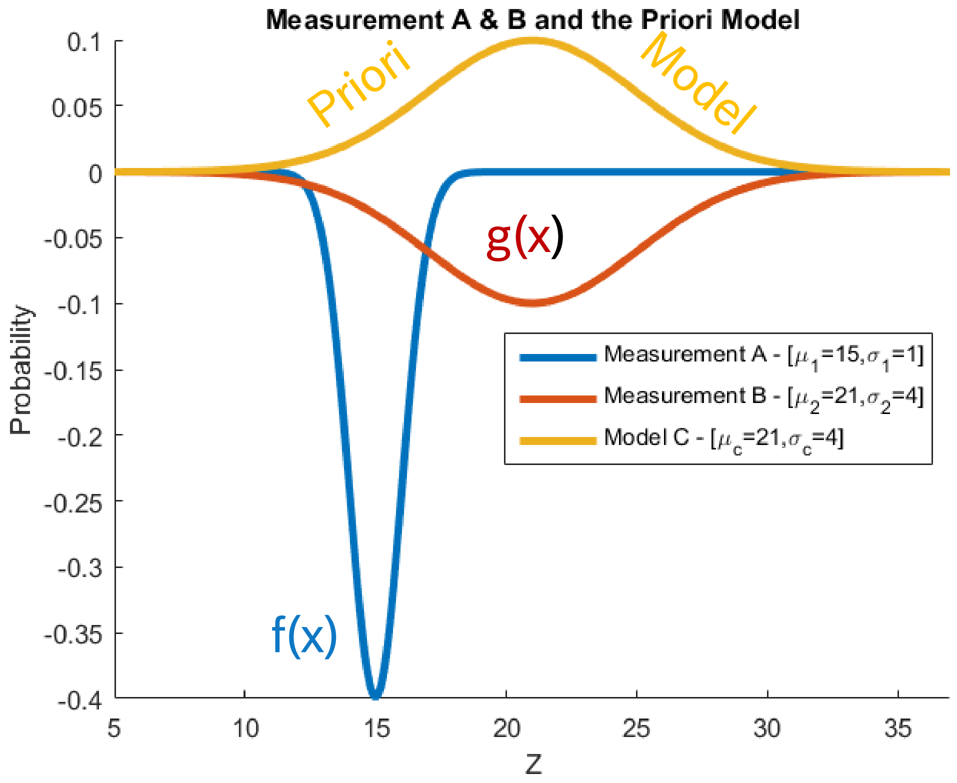
$$P(A = x_1 \; and \; B = \; x_2 | Priori \; is \; model \; A)$$
$$= P(A = x_1 \; | Model \; A) P(B = \; x_2 \; | Model \; A)$$
$$= \sum_i P(A = x_1 | R = x_i) P(R = x_i) \sum_i P(B = x_2 | R$$



Likelihood of the measurements
Priori beleif is the Measurement B

$$P(A = x_1 \; and \; B = \; x_2 | Priori \; is \; model \; C) = ?$$

$$P(A = x_1 \; and \; B = \; x_2 | Priori \; is \; model \; B)$$
$$= \; P(A = x_1 \; | Model \; B) P(B = \; x_2 \; | Model \; B)$$
$$= \sum_i P(A = x_1 | R = x_i) P(R = x_i) \sum_i P(B = x_2 | R$$



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Likelihood of the measurements
Which Priori Model would give the maximum likelihood?

$P(A = x_1 \; and \; B = \; x_2 | Priori \; is \; model \; C)$ Model C is a Gaussian with mean x_c and σ_c.

$$P(A = x_1 \; and \; B = \; x_2 | Model \; C) = \; P(A = x_1 \; | Model \; C) P(B = \; x_2 \; | Model \; C)$$

$$= \sum_i P(A = x_1 | R = x_i) P(R = x_i) \sum_i P(B = x_2 | R = x_i) P(R = x_i)$$

$$= \int_{-\infty}^{\infty} \Big[x, \sigma_1]]|_{x_1} [x_c, \sigma_c]]|_x dx \int_{-\infty}^{\infty} [x, \sigma_2]]|_{x_2} [x_c, \sigma_c]]|_x dx$$

$$= \int_{-\infty}^{\infty} \Big[x_1, \sigma_1]]|_x [x_c, \sigma_c]]|_x dx \int_{-\infty}^{\infty} [x_2, \sigma_2]]|_x [x_c, \sigma_c]]|_x dx = \Big[x_1, \sqrt{{\sigma_1}^2 + {\sigma_c}^2} \Big] |_{x_c} \Big[x_2, \sqrt{{\sigma_2}^2 + {\sigma_c}^2} \Big] |_{x_c}$$

$$= [\sqrt{\frac{({\sigma_1}^2 + {\sigma_c}^2)({\sigma_2}^2 + {\sigma_c}^2)}{({\sigma_1}^2 + {\sigma_c}^2) + ({\sigma_2}^2 + {\sigma_c}^2)}}, \frac{x_2({\sigma_1}^2 + {\sigma_c}^2) + x_1({\sigma_2}^2 + {\sigma_c}^2)}{({\sigma_1}^2 + {\sigma_c}^2) + ({\sigma_2}^2 + {\sigma_c}^2)}]|_{x_c}$$

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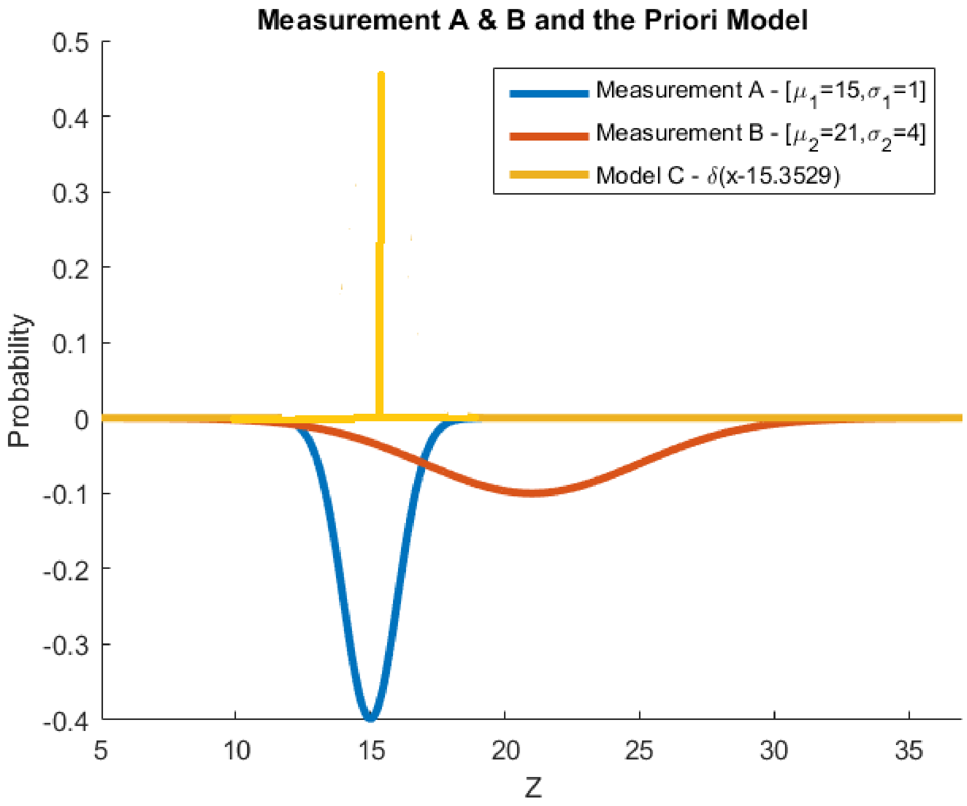
Likelihood of the measurements

Which Priori Model would give the maximum likelihood?

$$\min\left(\frac{({\sigma_1}^2+{\sigma_c}^2)({\sigma_2}^2+{\sigma_c}^2)}{({\sigma_1}^2+{\sigma_c}^2)+({\sigma_2}^2+{\sigma_c}^2)}\right)\Rightarrow {\sigma_c}^2=0$$

$$\frac{x_2({\sigma_1}^2+{\sigma_c}^2)+x_1({\sigma_2}^2+{\sigma_c}^2)}{({\sigma_1}^2+{\sigma_c}^2)+({\sigma_2}^2+{\sigma_c}^2)}=\frac{x_2({\sigma_1}^2)+x_1({\sigma_2}^2)}{({\sigma_1}^2)+({\sigma_2}^2)}=x_c$$

$$\boxed{\lim_{\sigma\to 0}\frac{1}{\sqrt{2\pi}\sigma}e^{-\frac{1}{2}\frac{(x-\mu)^2}{\sigma^2}}=\delta(x-\mu)}$$



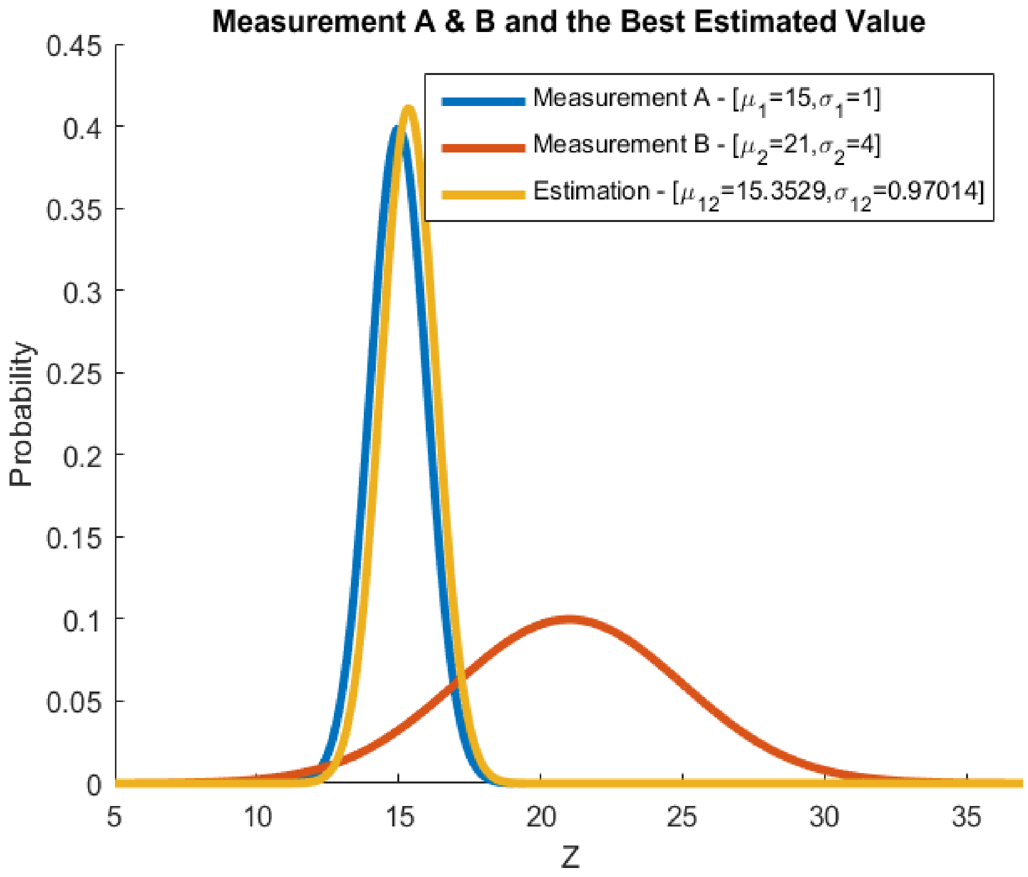
Maximum likelihood

But wouldn't we get the same result with a Kalman filter or LSQ?

$$P(Priori\ D\ at\ \mu | A = x_1\ and\ B = x_2)$$

$$= \frac{\left[x_1, \sqrt{{\sigma_1}^2 + {\sigma_2}^2}\right]\|_{x_2}[x_{12}, \sigma_{12}]\|_{\mu}}{\int_{-\infty}^{\infty}\left[x_1, \sqrt{{\sigma_1}^2 + {\sigma_2}^2}\right]\|_{x_2}[x_{12}, \sigma_{12}]\|_{x} dx}$$

$$= \frac{\left[x_1, \sqrt{{\sigma_1}^2 + {\sigma_2}^2}\right]\|_{x_2}[x_{12}, \sigma_{12}]\|_{\mu}}{\left[x_1, \sqrt{{\sigma_1}^2 + {\sigma_2}^2}\right]\|_{x_2}} = [x_{12}, \sigma_{12}]\|_{\mu}$$



Next Steps
Think Tank

THANK YOU