GENIVI Alliance

GENIVI Document CS00063

EnhancedPositionService

Component Specification

Accepted Version 5.0.0

25-01-2017

Sponsored by:
GENIVI Alliance

Abstract:
This document provides the Component Specification for the EnhancedPositionService

Keywords:
GENIVI, EnhancedPositionService, GPS, GNSS, Sensors, Dead-Reckoning.

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Revision History

The following table shows the revision history for this document.

Document Revision History

Date	Version	Author	Description
10-Dec-2014	3.0.0-alpha	Marco Residori, XS Embedded (now part of Mentor Graphics)	Updated API documentation and sequence diagrams. This is the first version of this document that uses the new GENIVI component specification template. Improvements after EG-LBS review
19-Jan-2015	3.0.0-alpha	Helmut Schmidt Continental Automotive GmbH	Update text according remaining review comments
21.Jan-2015	3.0.0	Marco Residori, XS Embedded (now part of Mentor Graphics)	Changed status to “Accepted”
16-Dec-2015	4.0.0-alpha	Marco Residori, Mentor Graphics	Updated API documentation in preparation to Release 4.0.0
25-Jan-2016	4.0.0	Marco Residori, Mentor Graphics	Release 4.0.0
11-Feb-2016	4.0.0	Marco Residori, Mentor Graphics	Updated document ID (26 → 51) as requested by SAT
23-Jun-2016	4.0.0	Marco Residori, Mentor Graphics	Fixed ticket GT-3345 (interface description layout generated from XML files). Corrected some links to Git repositories.
25-Jan-2017	5.0.0	Marco Residori, Mentor Graphics	Updated API documentation in preparation to Release 5.0.0 API documentation generated from Franca fidl files using Doxygen.

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1 Introduction

1.1 System Overview

The GENIVI Software Platform is a platform consisting of standardized middleware, application layer interfaces and frameworks defined or adopted by the GENIVI Alliance.

1.2 Component Overview

The EnhancedPositionService is a software component of the above mentioned GENIVI Software Platform that offers positioning information to client applications.

To calculate the current vehicle position, data from a GNSS receiver (e.g. GPS data) and available vehicle sensors (e.g. gyroscope and wheel ticks) are taken into account (dead-reckoning). In this way the EnhancedPositionService can calculate the current position even on roads, where the GNSS signal is too weak (e.g. in a tunnel, or in a parking garage) or too inaccurate (e.g. in a city or in a canyon).

1.3 Document Overview

This document describes the architecture and the interface of the GENIVI EnhancedPositionService.

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2 References

The following standards and specifications contain provisions, which through reference in this document constitute provisions of this specification. All the standards and specifications listed are normative references. At the time of publication, the editions indicated were valid. All standards and specifications are subject to revision, and parties to agreements based on this specification are encouraged to investigate the possibility of applying the most recent editions of the standards and specifications indicated below.

[1] "GENIVI GNSSService – Component Specification" - https://github.com/GENIVI/positioning/tree/master/gnss-service/doc

[2] "GENIVI SensorsService – Component Specification" – https://github.com/GENIVI/positioning/tree/master/sensors-service/doc

[3] GENIVI UML Model - https://svn.genivi.org/uml-model/genivi/trunk

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3 Glossary

Acronym	Term	Definition
GNSS	Global Navigation Satellite System	GNSS is a space-based satellite navigation system that provides location and time information.
GPS	Global Positioning System	GPS is a space-based GNSS maintained by the United States government.
GLONASS	Globalnaya navigatsionnaya sputnikovaya sistema	GLONASS is a space-based GNSS operated by the Russian Aerospace Defence Forces.
BDS	BeiDou Navigation Satellite System	BDS is a Chinese GNSS, also known as COMPASS.
	Galileo	Galileo is a GNSS currently being built by the European Union (EU) and European Space Agency (ESA).
	Vehicle Sensors	Vehicle sensors are sensors used for positioning calculation which are located either in the vehicle itself or directly in the unit where the EnhancedPositionService is deployed. Examples are Gyroscopes, Accelerometers, wheel tick or vehicle speed sensors.
DR	Dead Reckoning	In strict sense: A technique that calculates the current position of a vehicle by integrating the relative changes in heading and distance over time since leaving a known starting point. The starting point can be determined e.g. from a GNSS system and the heading and distance changes can be determined from the vehicle sensors. In a more common sense: The fusion of GNSS and vehicle sensor data to calculate improved position and velocity. I.e. even when a GNSS fix is available.

Table 1 – Acronym and Term Definitions

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4 Requirements

The requirements related to the EnhancedPositionService are located in the GENIVI UML model (see [3]) in the package *GENIVI Model/LogicalView/SW Platform requirements/Location Based Services/Positioning.*

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5 Constraints and Assumptions

This is a handwritten chapter that summarizes the constraints and assumptions done in the project for the component.

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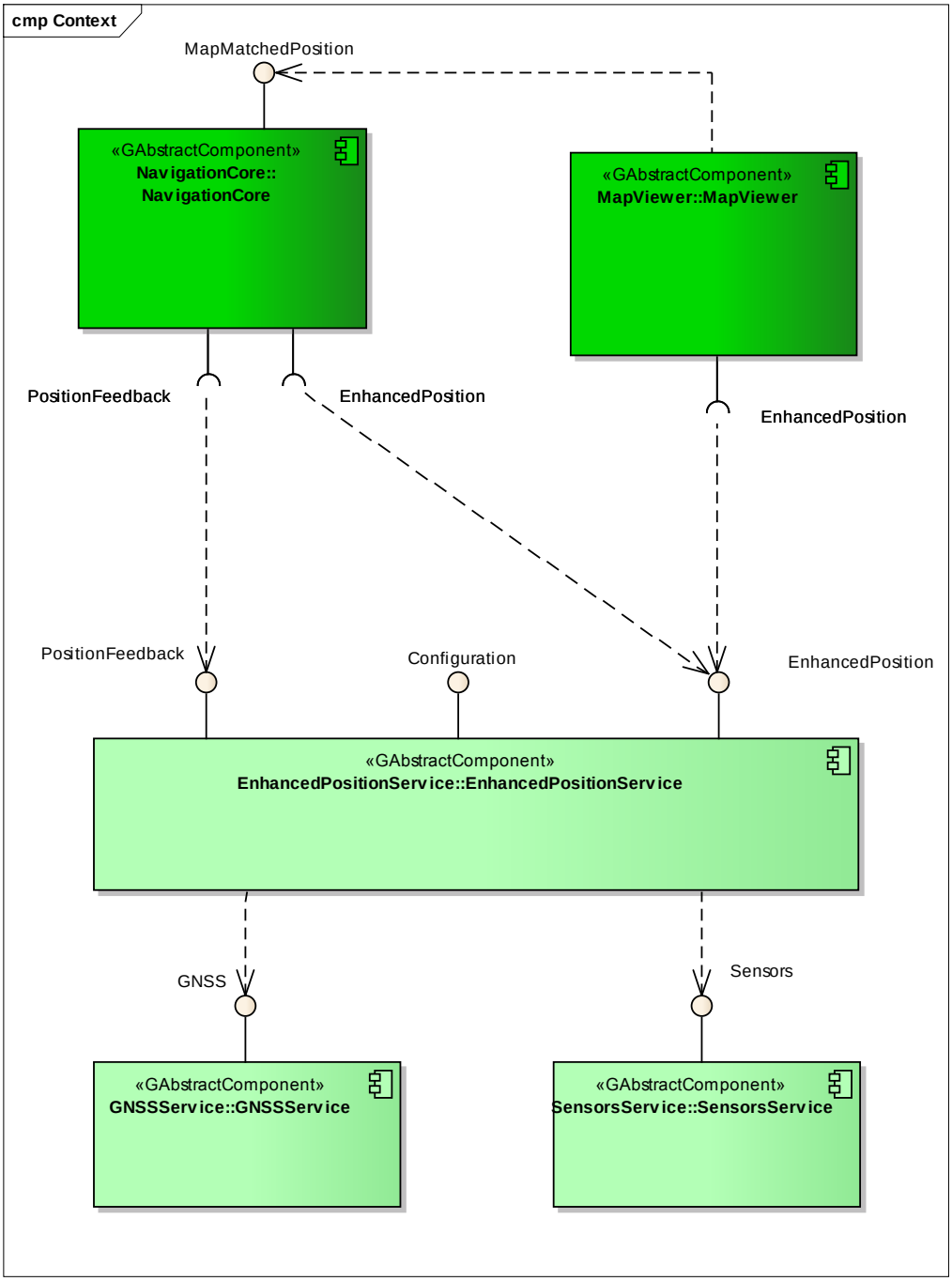
6 Architecture

The information in this chapter is provided only for information purpose; this is not a normative part.

6.1 Architecture Overview

The following component diagram shows how the EnhancedPositionService interacts with other GENIVI components:

- GNSSService (C library)
- SensorsService (C library)
- NavigationCore (example of client application)
- MapViewer (example of client application)



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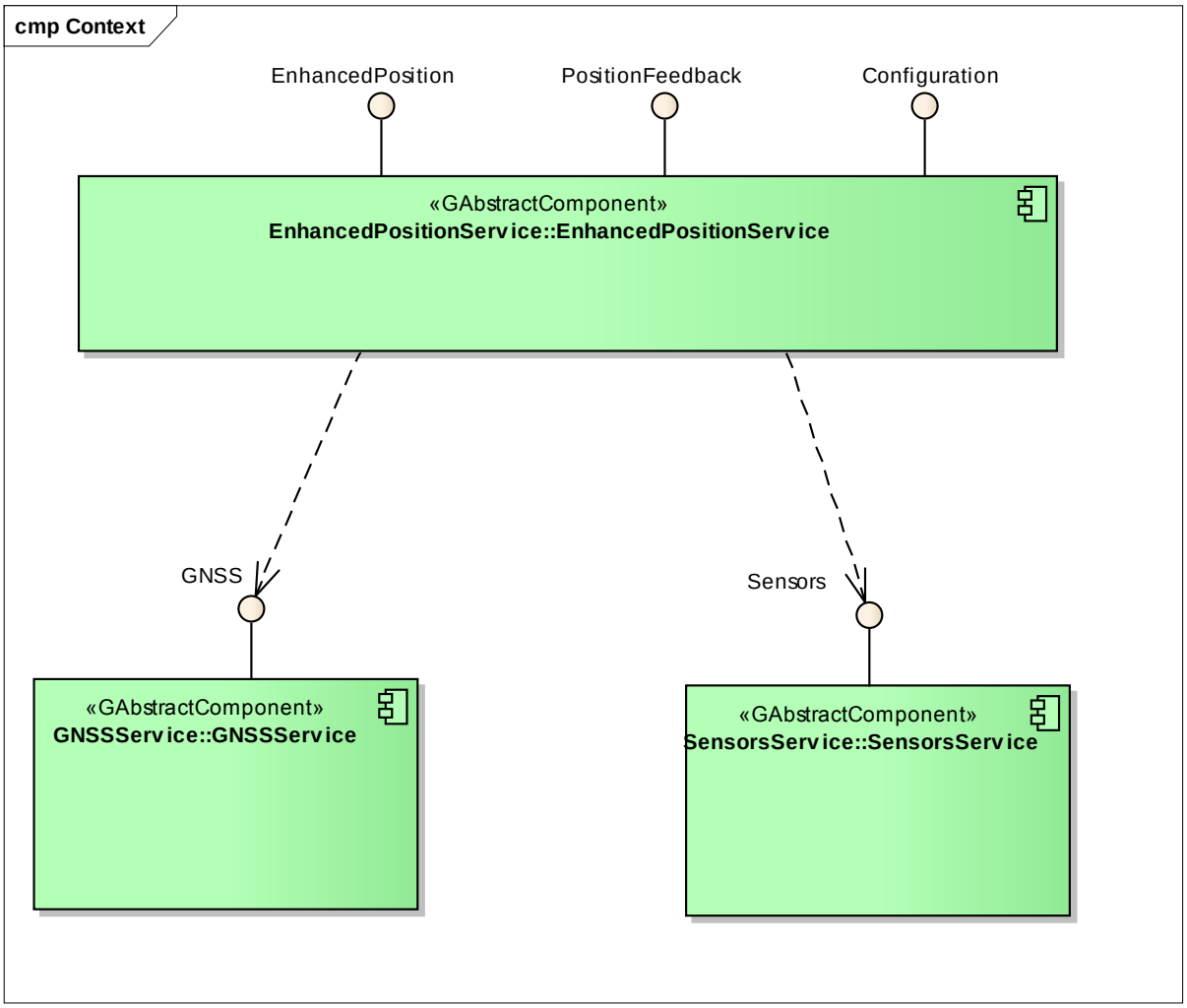
6.1.1 Component Dependencies

The EnhancedPositionService depends on the following GENIVI components:

- GNSSService (library)
- SensorsService (library)



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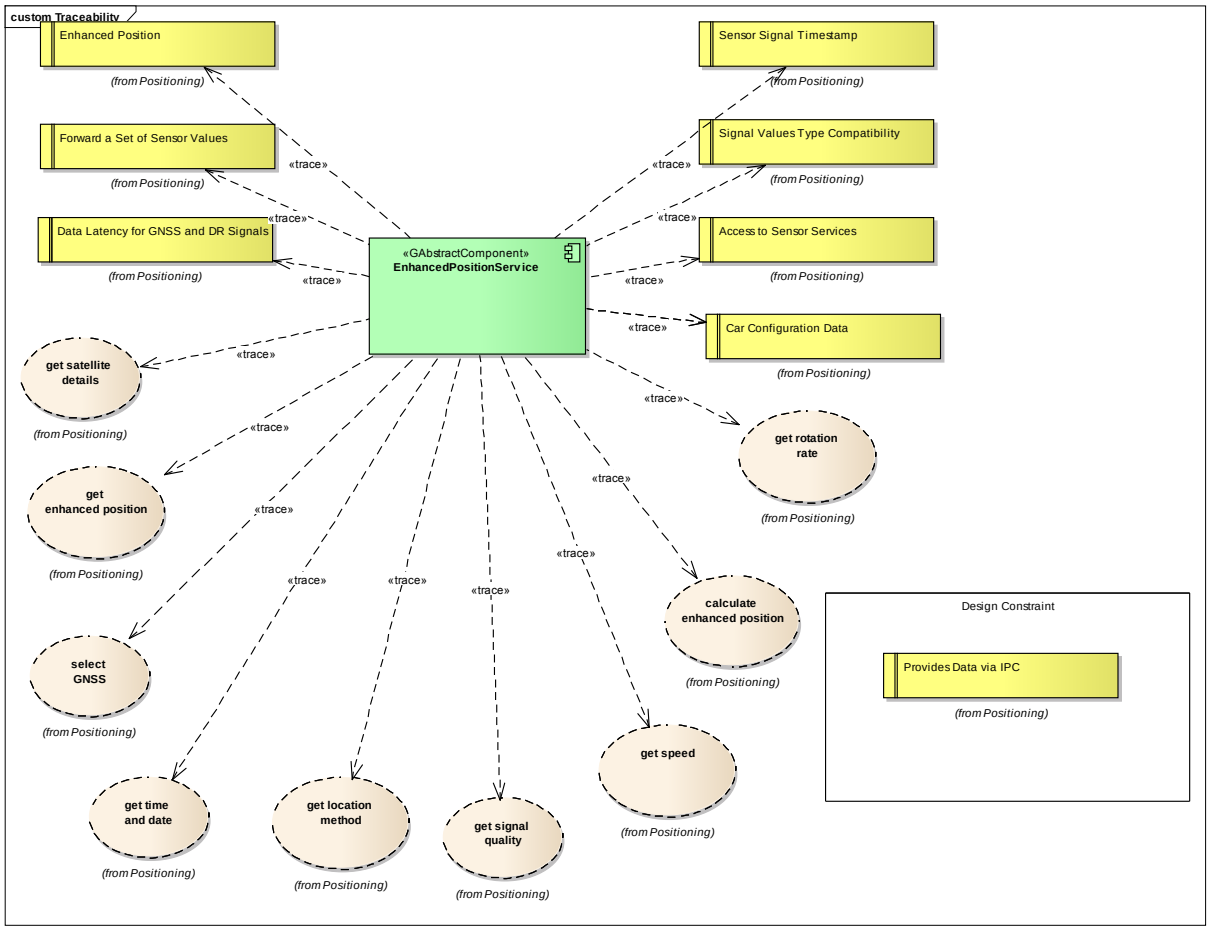
6.1.2 Component Traceability

The following diagrams shows to which requirements and use cases realizations the EnhancedPositionService is traced to:



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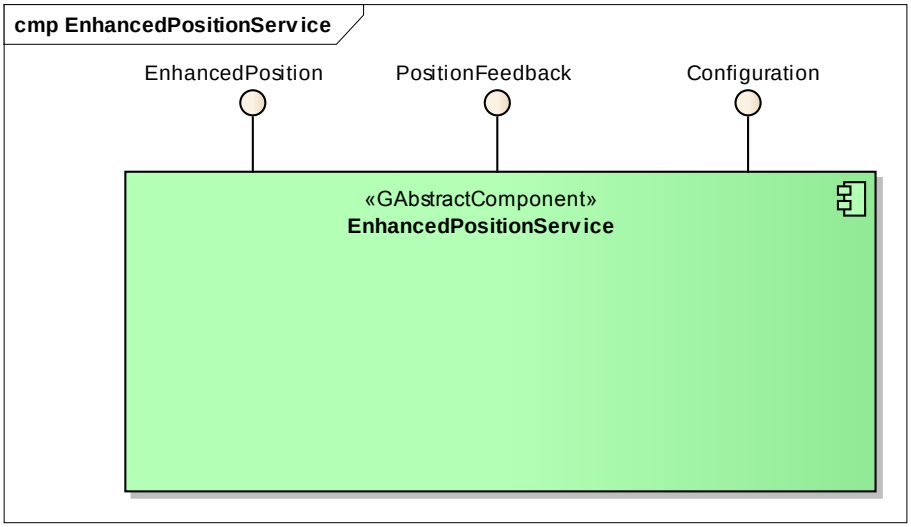
6.2 EnhancedPositionService



6.2.1 Responsibility and Features

The EnhancedPositionService is a software component that offers positioning information to client applications.

To calculate the current vehicle position, data from a GNSS receiver (e.g. GPS data) and available vehicle sensors (e.g. gyroscope and wheel ticks) are taken into account (dead-reckoning). In this way the EnhancedPositionService can calculate the current position even on roads, where the GNSS signal is too weak (e.g. in a tunnel, or in a parking garage).

The result of the map matching can be provided as feedback to this module by the NavigationCore component. This component is the main client of the GNSSService and of the SensorsService.

The EnhancedPositionService will be typically implemented as a multi-client daemon with a D-Bus interface.

6.2.2 Provided Interfaces

• **EnhancedPosition**: This interface provides a 'filtered' position that takes into account the value coming from the vehicle sensors (dead-reckoning).

• **PositionFeedback**: This interface offers methods that allows the NavigationCore to provide a position feedback to the EnhancedPositionService. The component that implements the Position-Feedback interface requires the data provided by a 'map matcher' (typically the NavigationCore component). The PositionFeedback is an added improvement which does not negatively affect systems that don´t support maps or have a map-matching feature.

• **Configuration**: This interface allows a client application to manage configuration parameters, like the GNSS type.

6.2.3 Required Interfaces

- **GNSS**: This interface abstracts the access to a GNSS device. Please see [1].
- **Sensors**: This interface abstracts the access to vehicle sensors. Please see [2].

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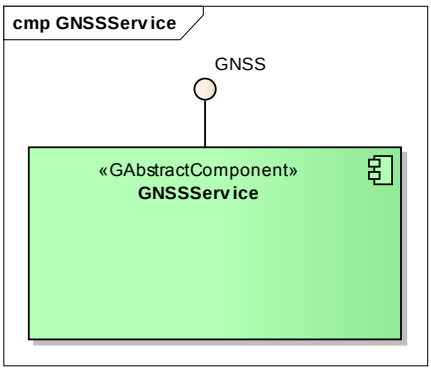
6.3 GNSSService



6.3.1 Responsibility and Features

The GNSSService is a component that retrieves positioning data from a GNSS receiver (e.g. NMEA sentences from a GPS receiver) and presents them to its client applications.

The GNSSService will be typically implemented as a single-client library.

6.3.2 Provided Interfaces

The interfaces provided by this component are described at [1].

6.3.3 Required Interfaces

None.

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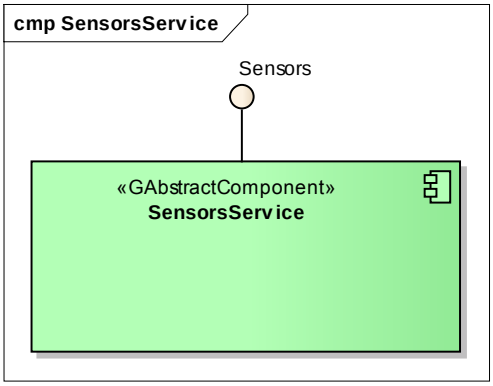
6.4 SensorsService



6.4.1 Responsibility and Features

The SensorsService is a component that retrieves sensor data from several vehicle sensors (e.g. gyroscope, wheel ticks) and presents them to its client applications.

The SensorsService will be typically implemented as a single-client library.

6.4.2 Provided Interfaces

The interfaces provided by this component are described at [2].

6.4.3 Required Interfaces

None.

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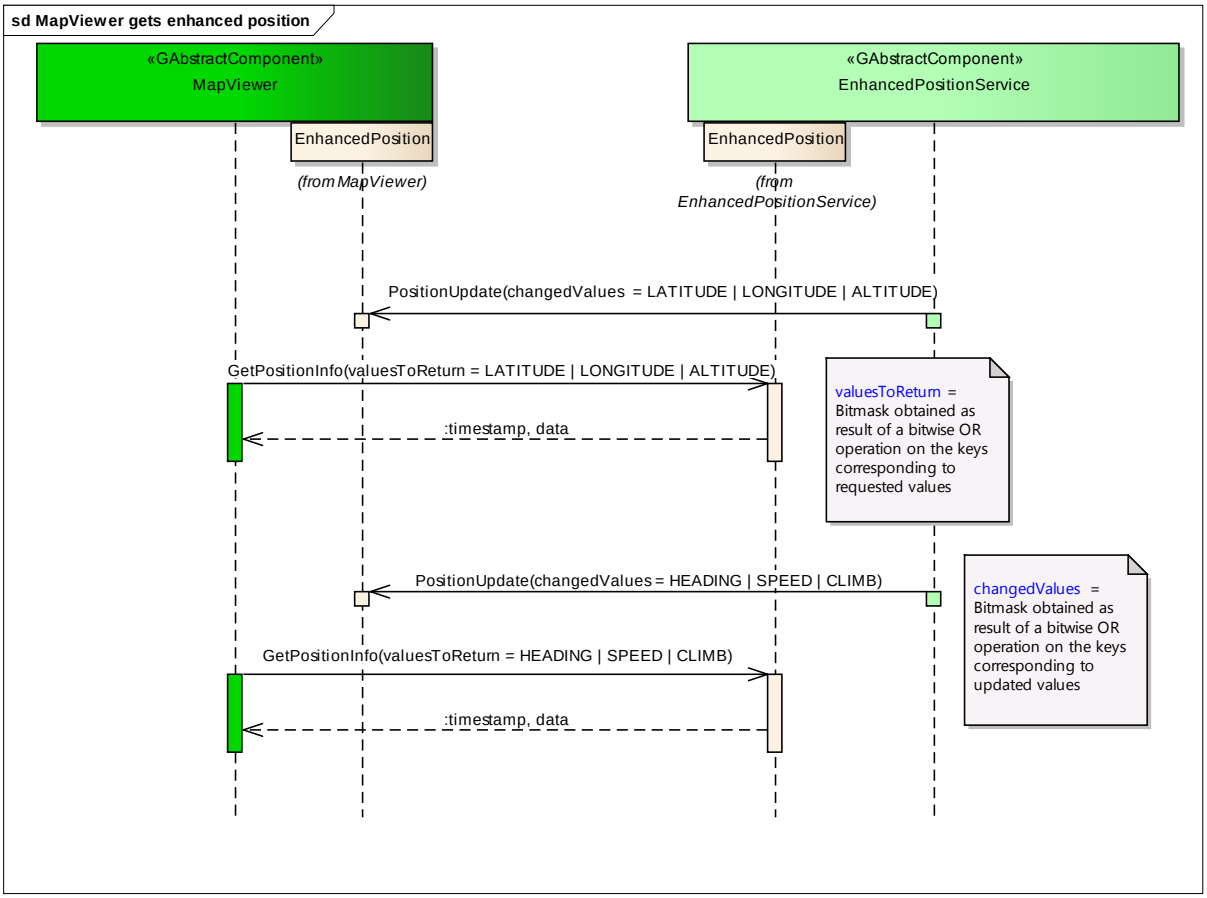
7 Collaboration

7.1 Get Enhanced Position

7.1.1 MapViewer retrieves enhanced position

The following sequence diagram describes how a client application can retrieve the vehicle position.



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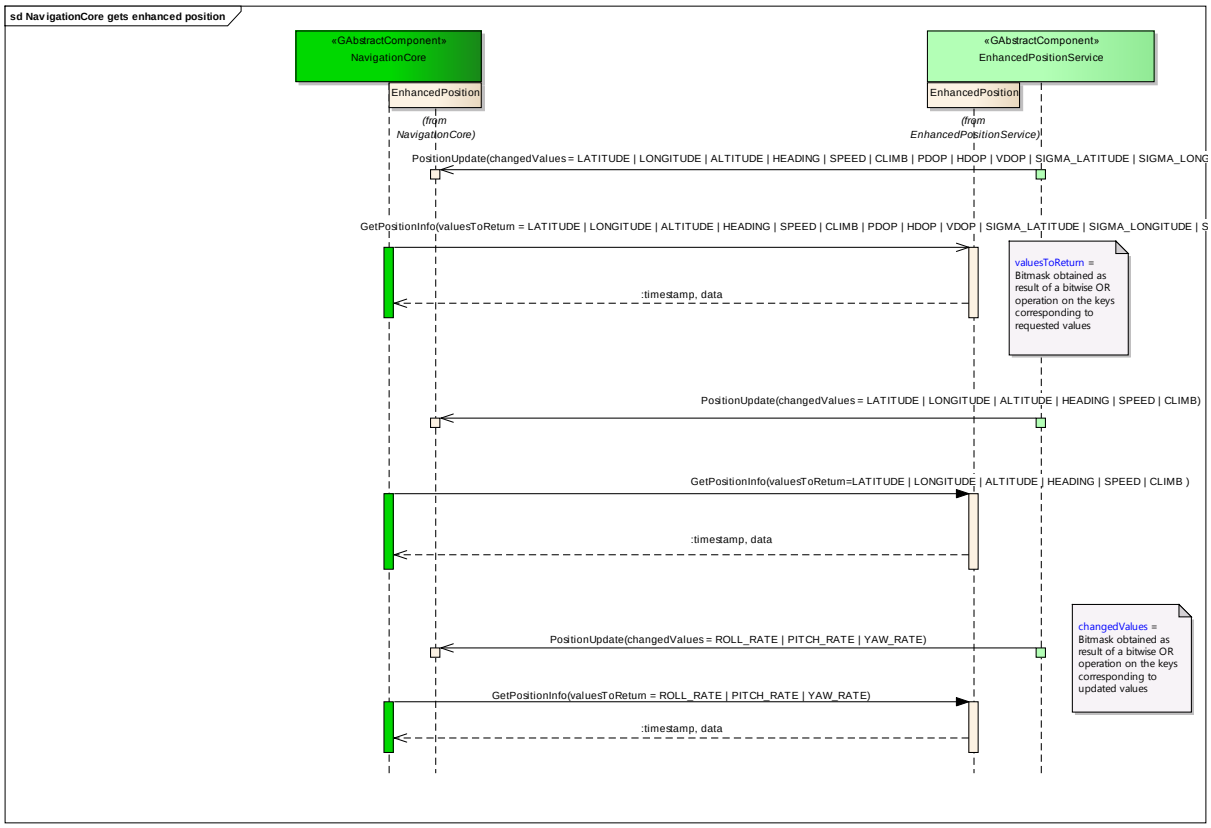
7.1.2 NavigationCore retrieves enhanced position

The following sequence diagram describes how a client application can retrieve the vehicle position.



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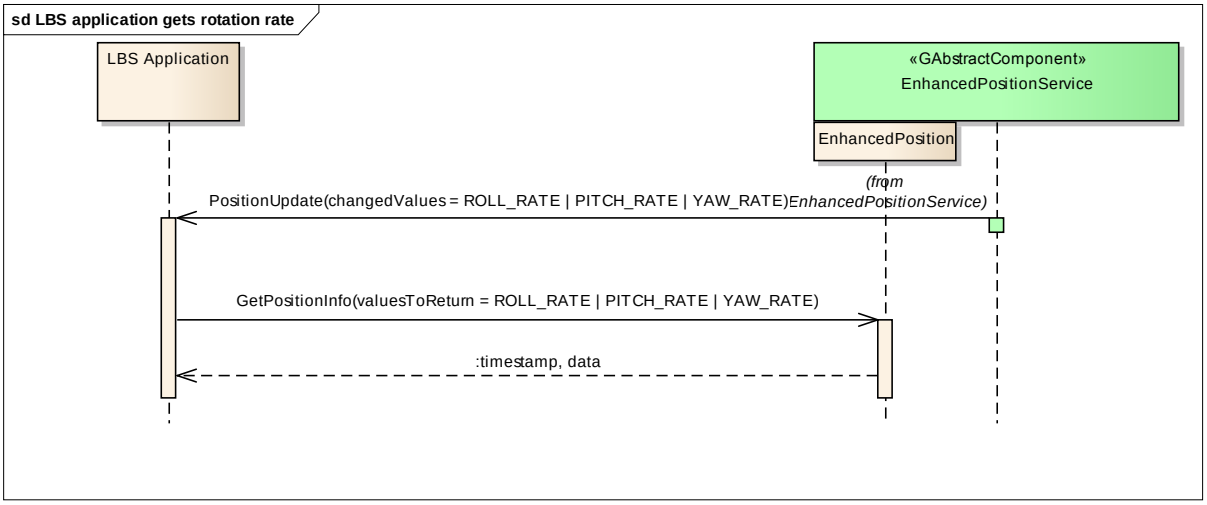
7.2 Get Rotation Rate

7.2.1 LBS Application retrieves rotation rate

The following sequence diagram describes how a client application can retrieve the vehicle rotation rate.



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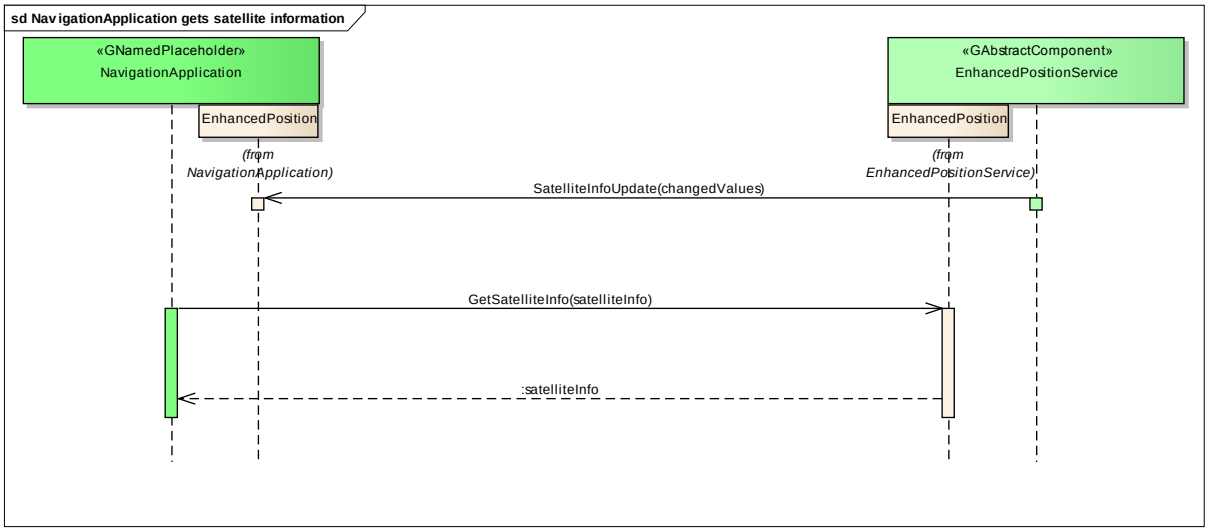
7.3 Get Satellite Details

7.3.1 Navigation Application retrieves satellite information

The following sequence diagram describes how a client application can retrieve satellite information.



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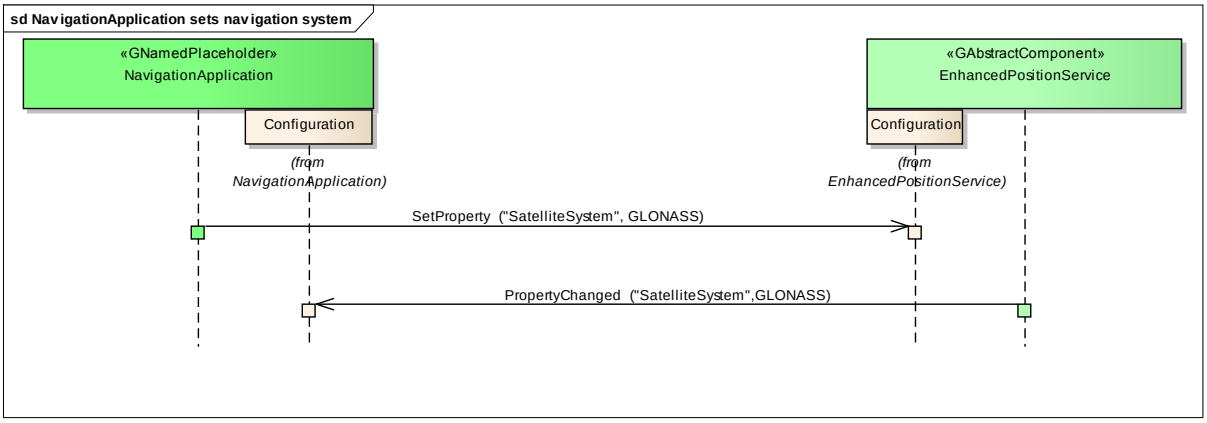
7.4 Set Navigation System

7.4.1 Navigation Application sets navigation system

The following sequence diagram describes how a client application can set the satellite system.



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8 Implementation

8.1 Available Implementation details

A Proof of concept (PoC) of the EnhancedPositionServiceis is available at:
https://github.com/GENIVI/positioning

8.2 Usage examples

Please see the examples contained in in the folder:
enhanced-position-service/franca/test/test-scripts

8.3 Test Plan

Please see: *positioning/enhanced-position-service/franca/doc/testplan.txt*

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9 Interfaces

The following pages describe the interfaces of the EnhancedPositionService.

9.1 Git Repository

The EnhancedPositionService interfaces can be found in the folder:
positioning/enhanced-position-service/franca/api/

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