

# Indoor Positioning Using the OpenHPS Framework

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# What is OpenHPS?



## An Open Source Hybrid Positioning System

OpenHPS

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Basic Concepts

Data Object

Data Frame

Creating data frames

Creating a custom data frame

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Data Frame

Data frames are envelopes that are transmitted and processed through a positioning model. These frames are created by source nodes (e.g. sensors) and contain one or more data objects needed to process the frame.

A frame should contain a single reading of a sensor (such as an image of a video stream or current acceleration) and not permanent or calculated information.

VideoDataFrame

uid

timestamp

source

CameraObject

uid: "camera", position: { x: 2, y: 5, z: 3 }, projection: ..., width: 1280, height: 1024

Image

DataObject

Detected object

DataObject

Detected object

DataObject

Detected object

IMUDataFrame

uid

timestamp

source

DataObject

uid: "imuSensor", position: { x: 0, y: 0, linearVelocity: { x: 1, y: 0 } }

Acceleration

Sensor Frequency

RDFDataFrame

uid

timestamp

source

RFRceiverObject

uid: "wifiScanner", relativePositions: [ { obj: "AP1", distance: 5 }, { obj: "AP2", distance: 8 } ]

AP1 DataObject

uid: "AP1", position: { x: 0, y: 0 }

AP2 DataObject

uid: "AP2", position: { x: 15, y: 3 }

Creating data frames

OpenHPS is a framework that processes sensor information to retrieve a position for one or more data objects. These objects are contained within an envelope called a data frame.

```
import { DataObject, DataFrame } from '@openhps/core';

const myObject = new DataObject("bsigner", "Beat Signer");
const frame = new DataFrame();
frame.addObject(myObject);
```

(method) DataFrame.addObject(object: DataObject): void

A basic data frame supports the addition of objects. Extended versions of this basic data frame also add additional sensor data.

Creating a custom data frame

Similar to data objects, decorators have to be used to indicate a serializable data frame.

```
import {
  DataFrame,
  SerializableObject,
  SerializableMember
} from '@openhps/core';

@SerializableObject()
export class QRDataFrame extends DataFrame {
  public rawImage: any = undefined;
}
```

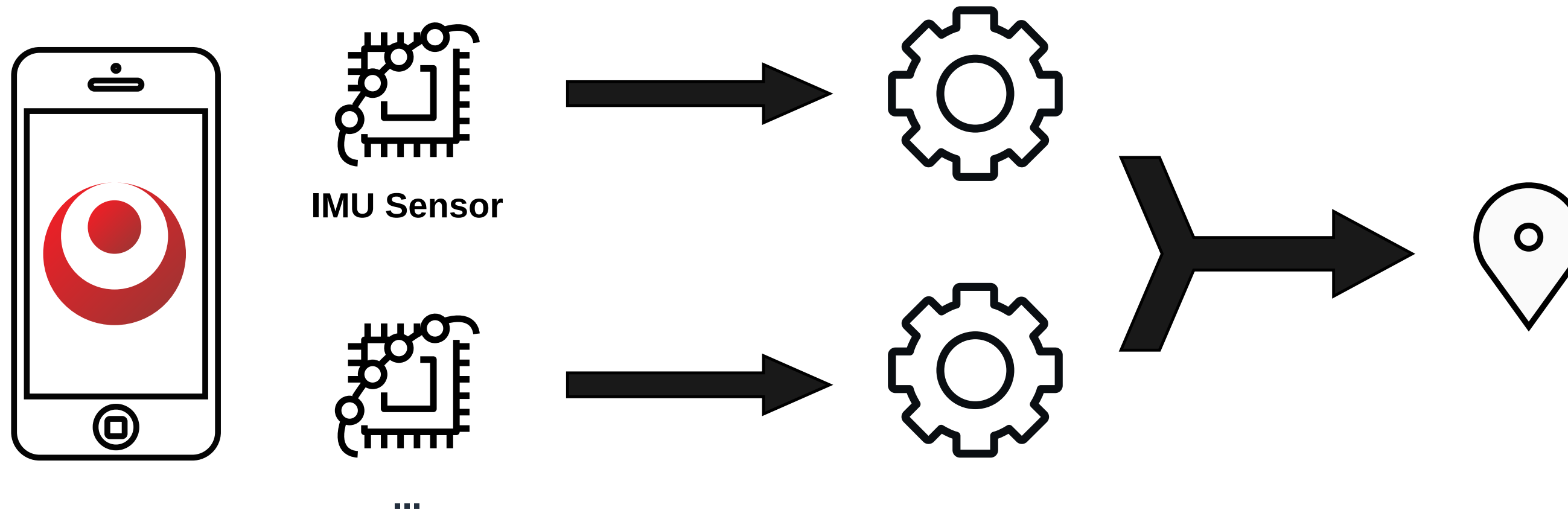
# What is OpenHPS?



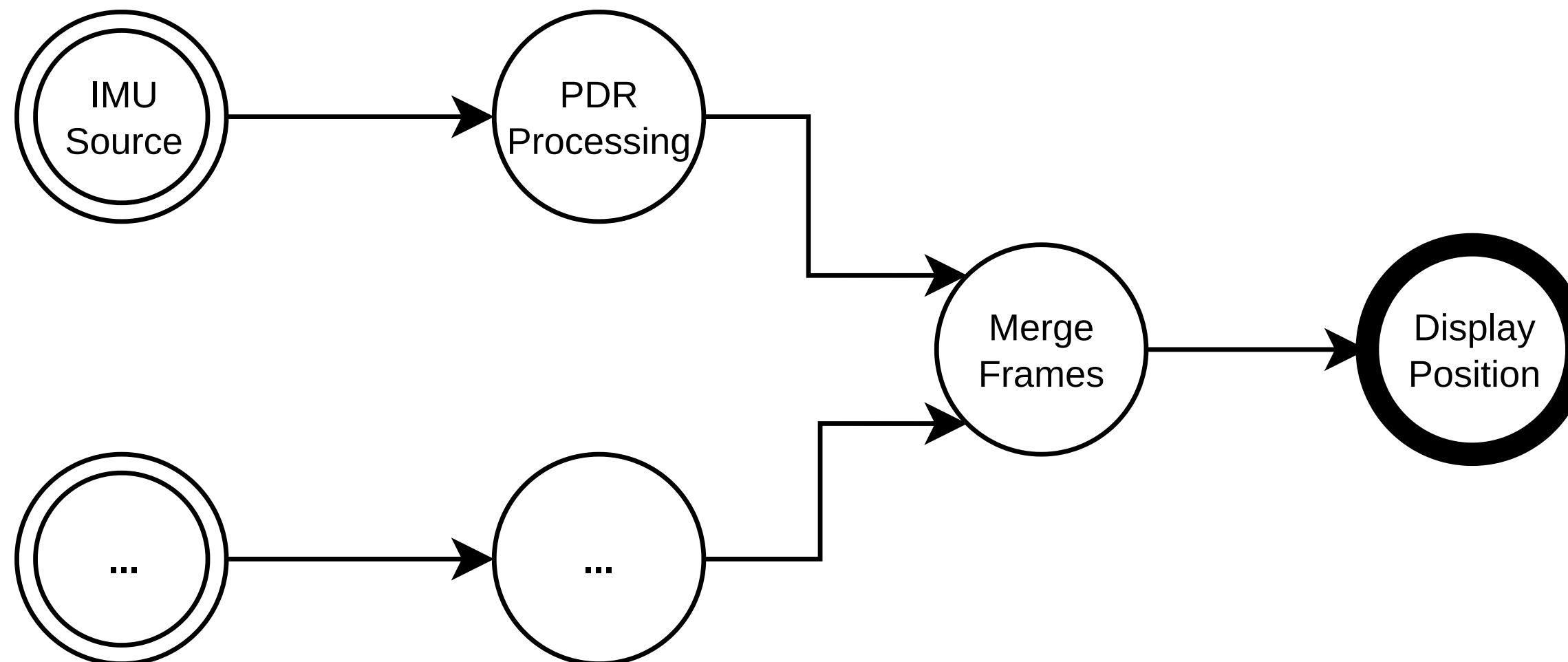
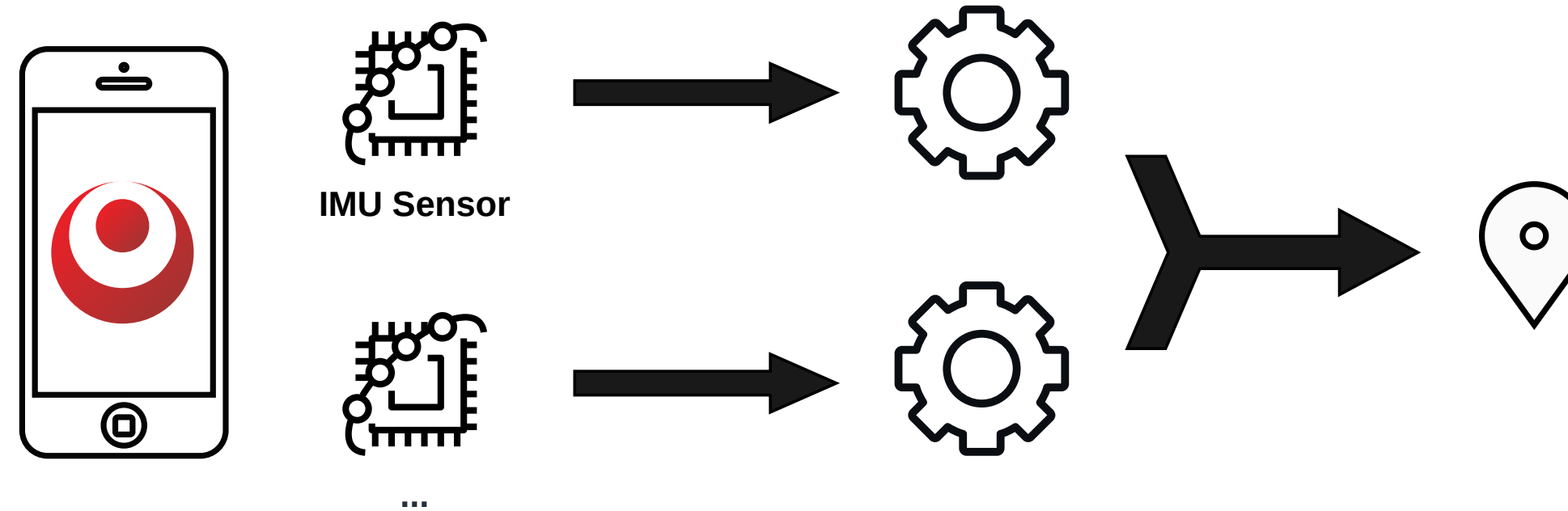
## An Open Source Hybrid Positioning System

- ▶ Any technology
- ▶ Any algorithm
- ▶ Various use cases
- ▶ Flexible processing and output
  - Accuracy over battery consumption, reliability, ...
- ▶ Aimed towards
  - Developers
  - Researchers

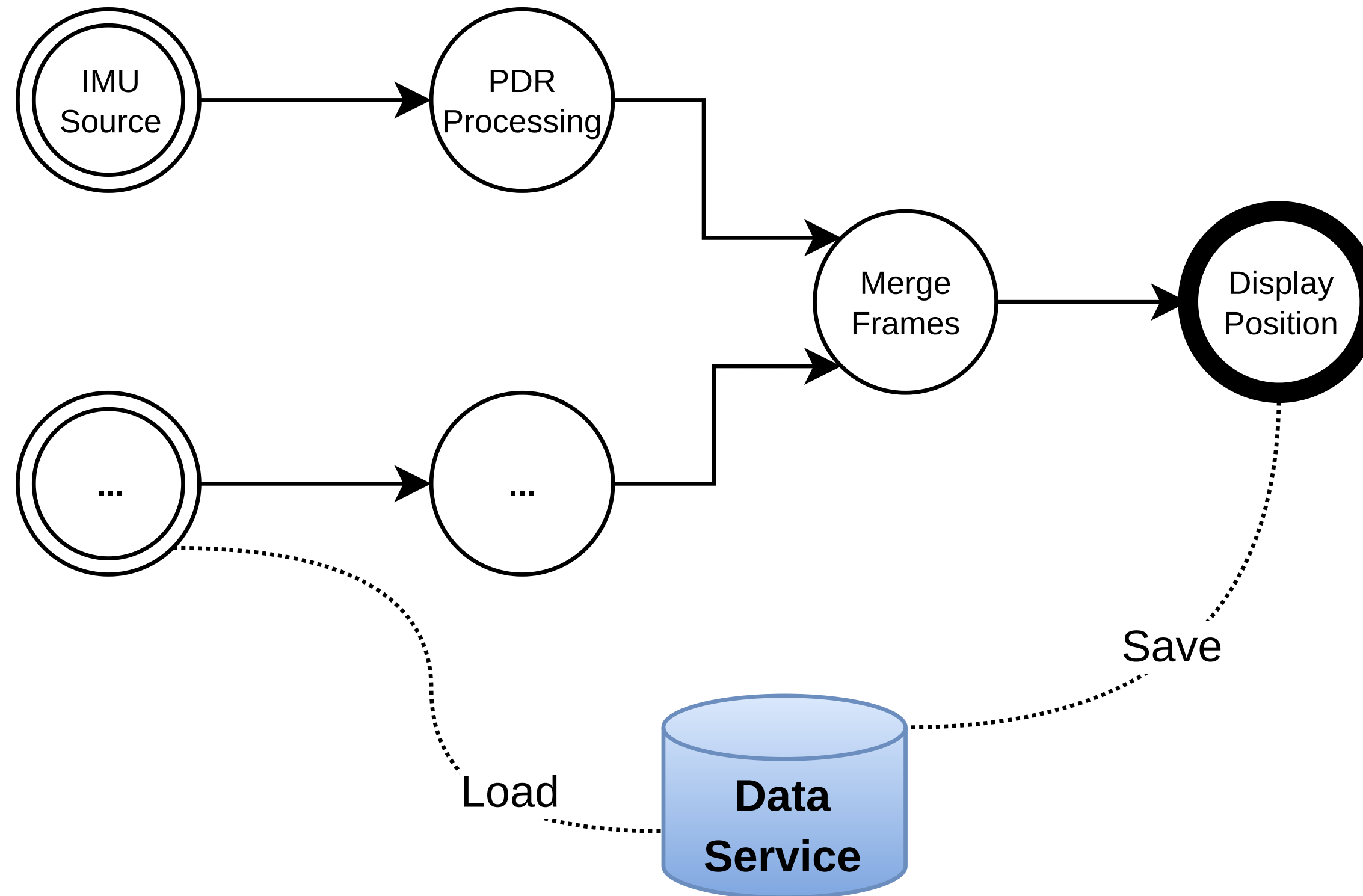
# Process Network Design



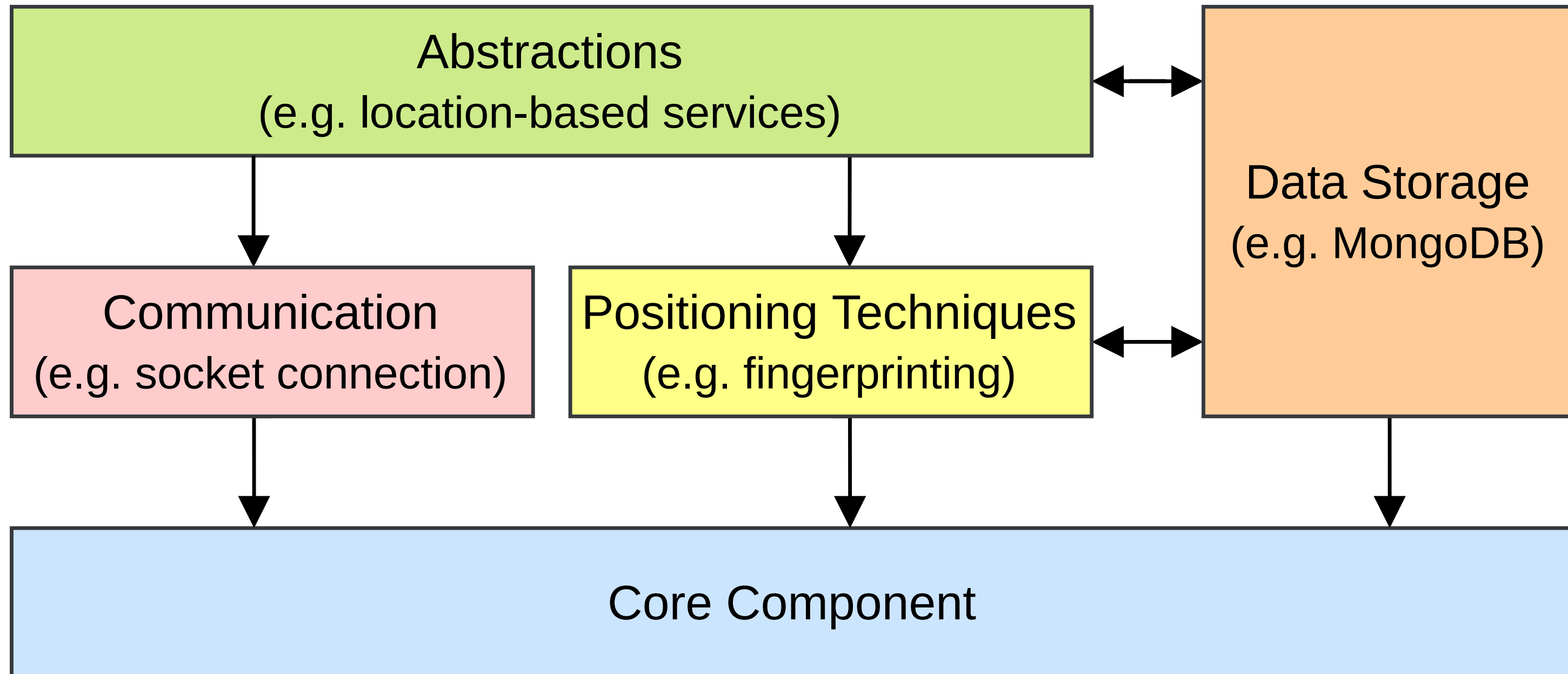
# Process Network Design ...



# Process Network Design ...



# Modularity



# Modularity ...

## **Communication**

Socket, MQTT, REST API, ...

## **Data Storage**

MongoDB, LocalStorage, RDF, ...

## **Positioning Algorithms**

IMU, fingerprinting, OpenVSLAM, ...

## **Abstractions**

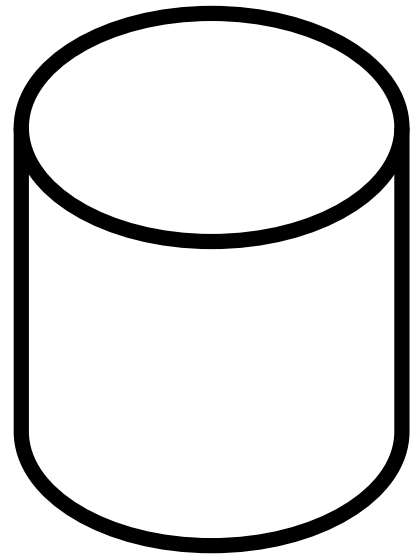
Geospatial, location-based services, geojson, ...

## **Other**

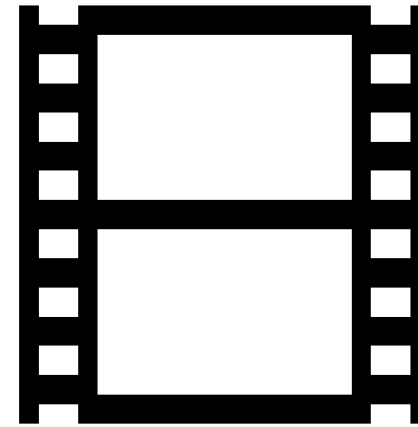
React-Native, NativeScript, Sphero, ...



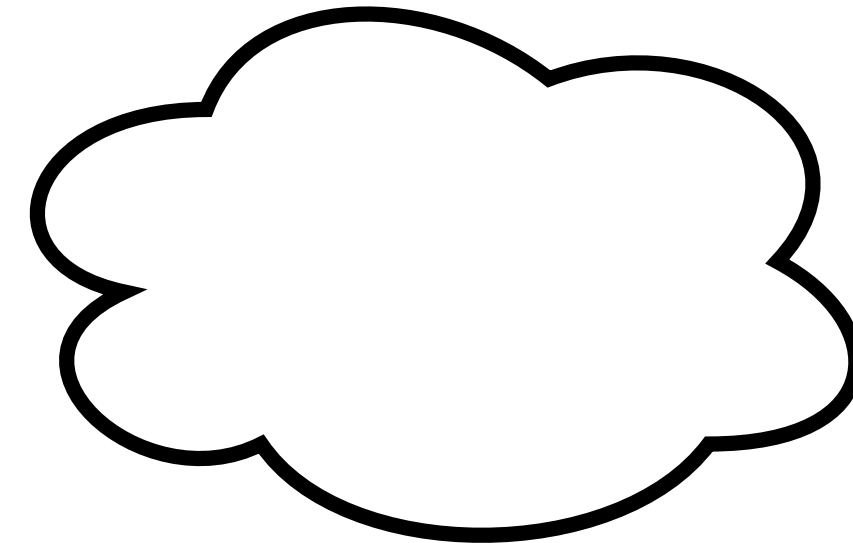
# Data Processing



**Knowledge**

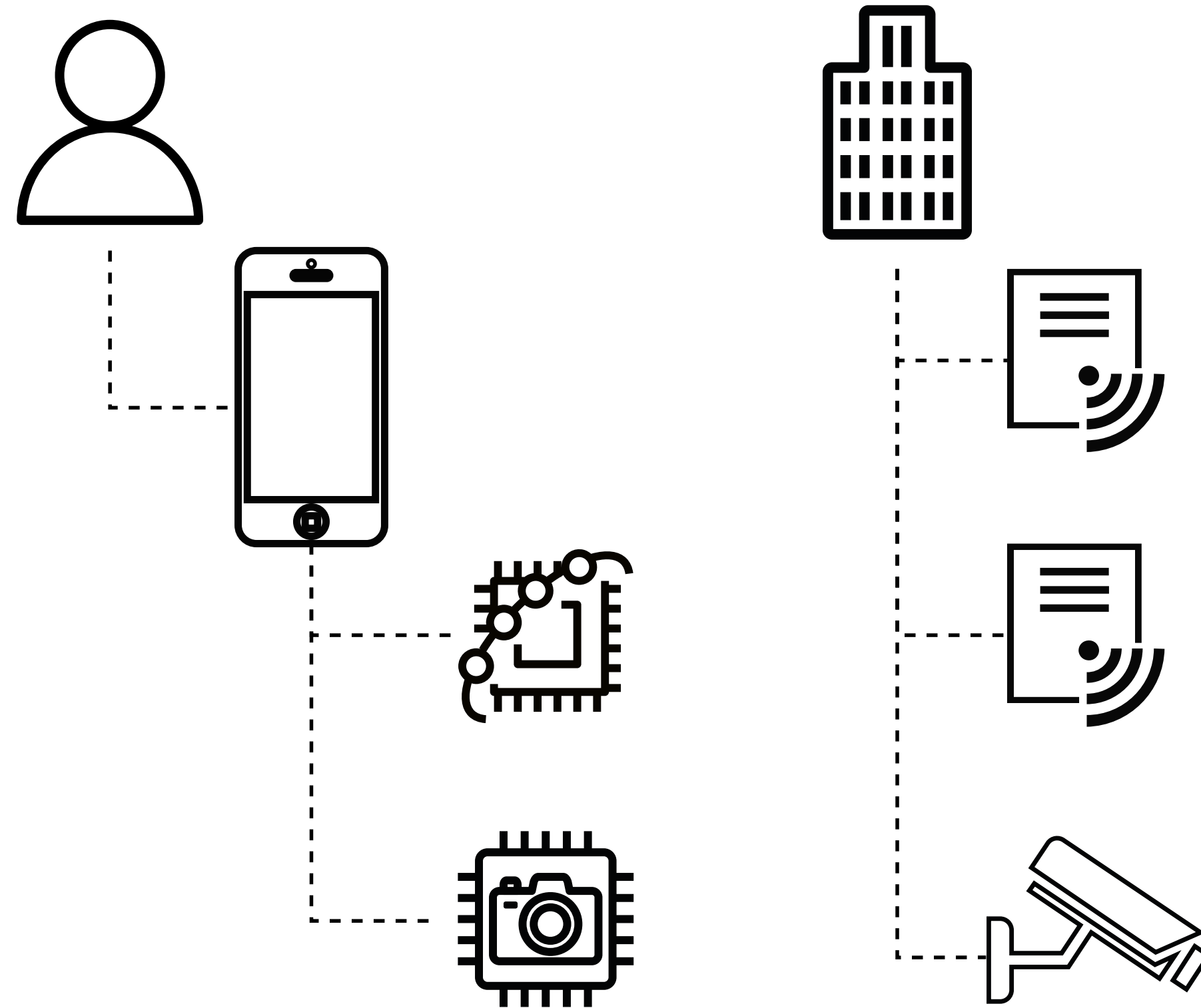


**Raw Data**



**Processed Data**

# DataObject



# Absolute and Relative Positions

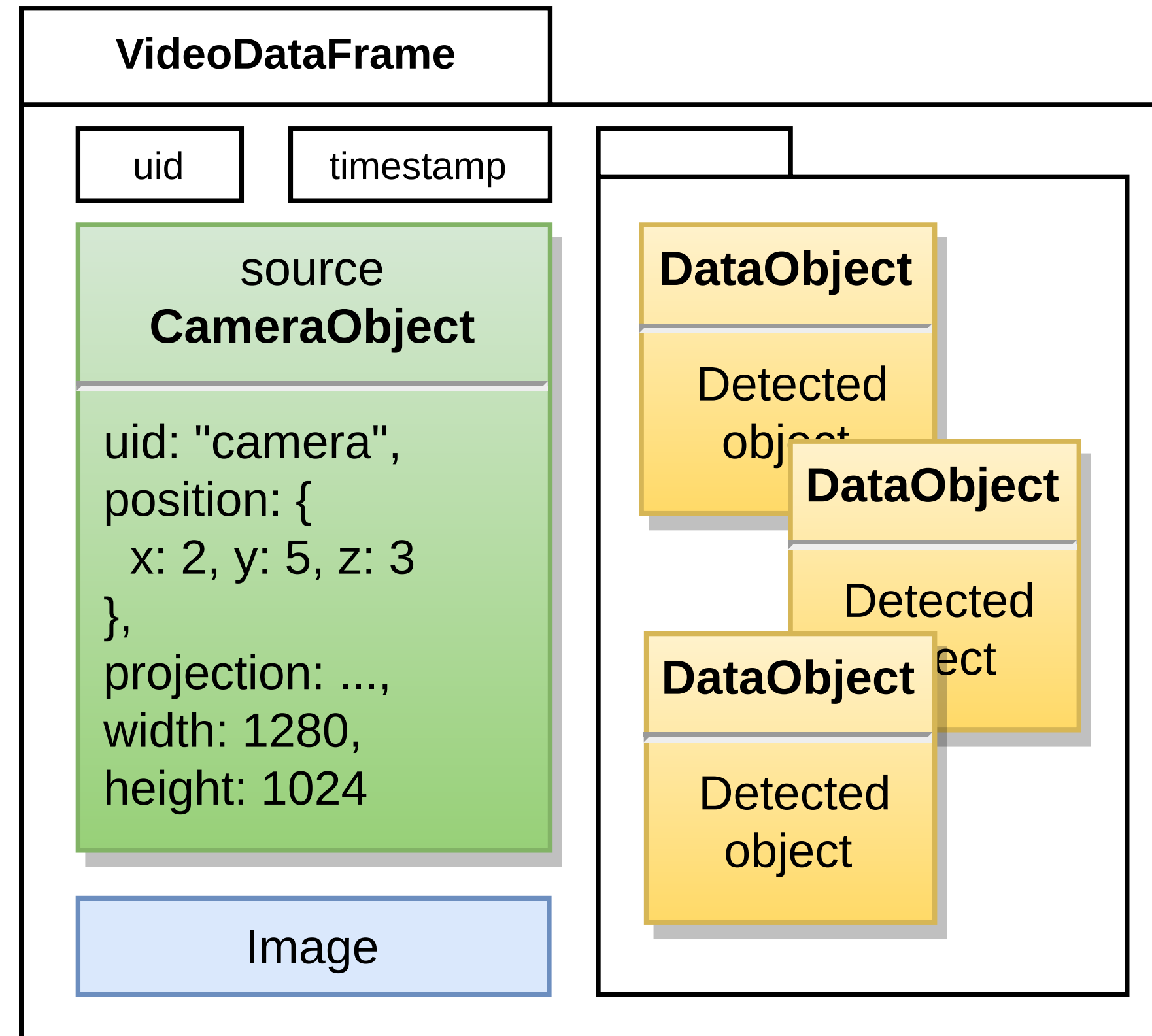
## Absolute

- ▶ 2D, 3D, Geographical, ...

## Relative

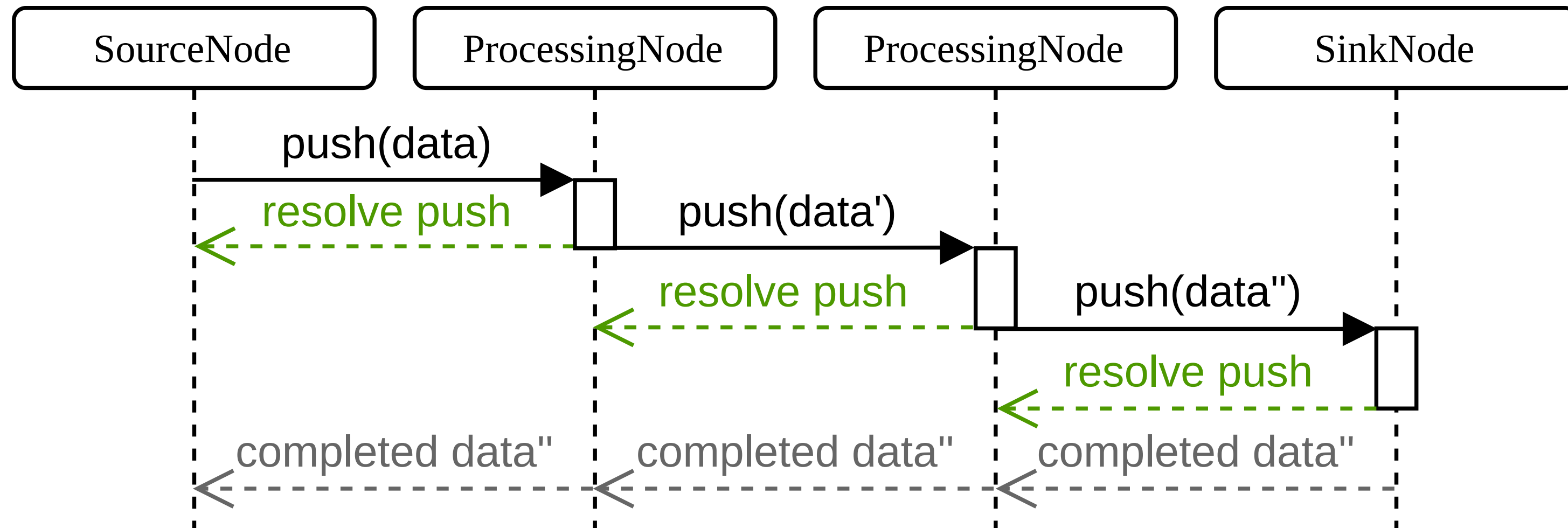
- ▶ Distance, angle, velocity, ...
- ▶ Relative to another *object*

# DataFrame



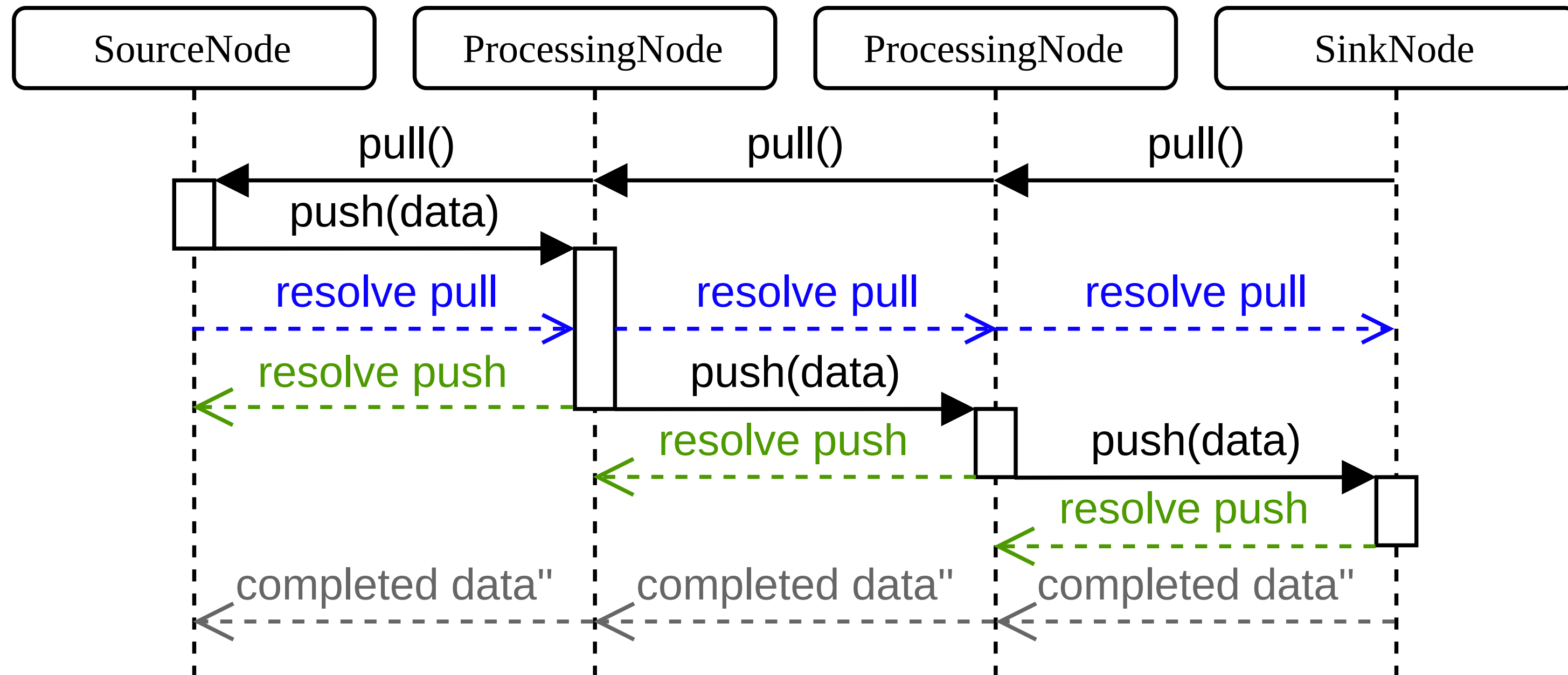
# DataFrame ...

## Pushing Data



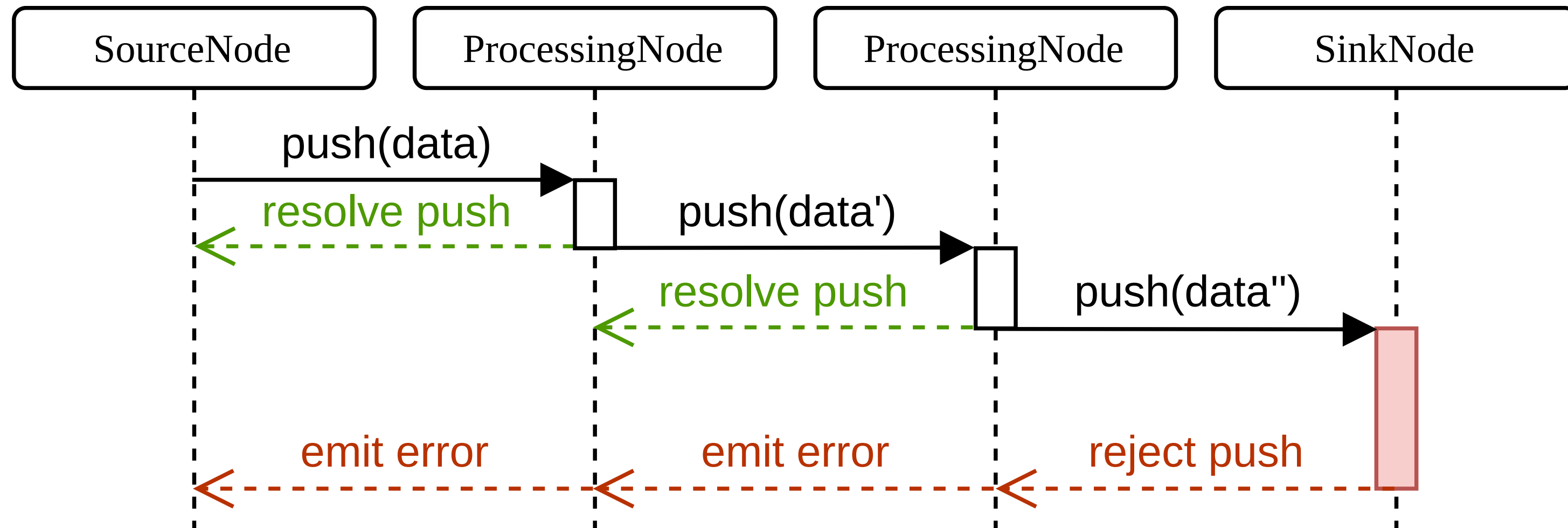
# DataFrame ...

## Pulling Data



# DataFrame ...

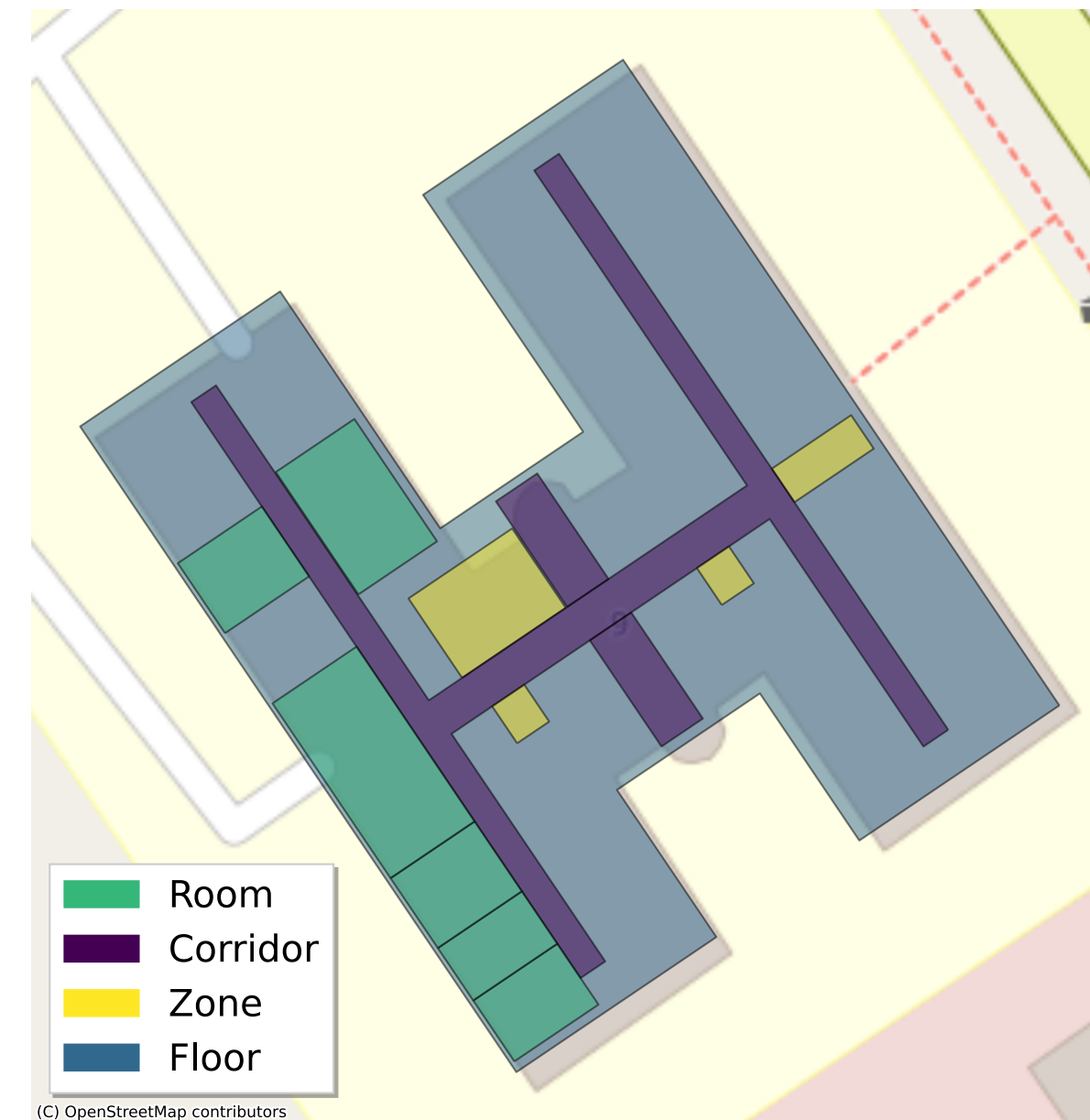
## Pushing Error



# SymbolicSpace

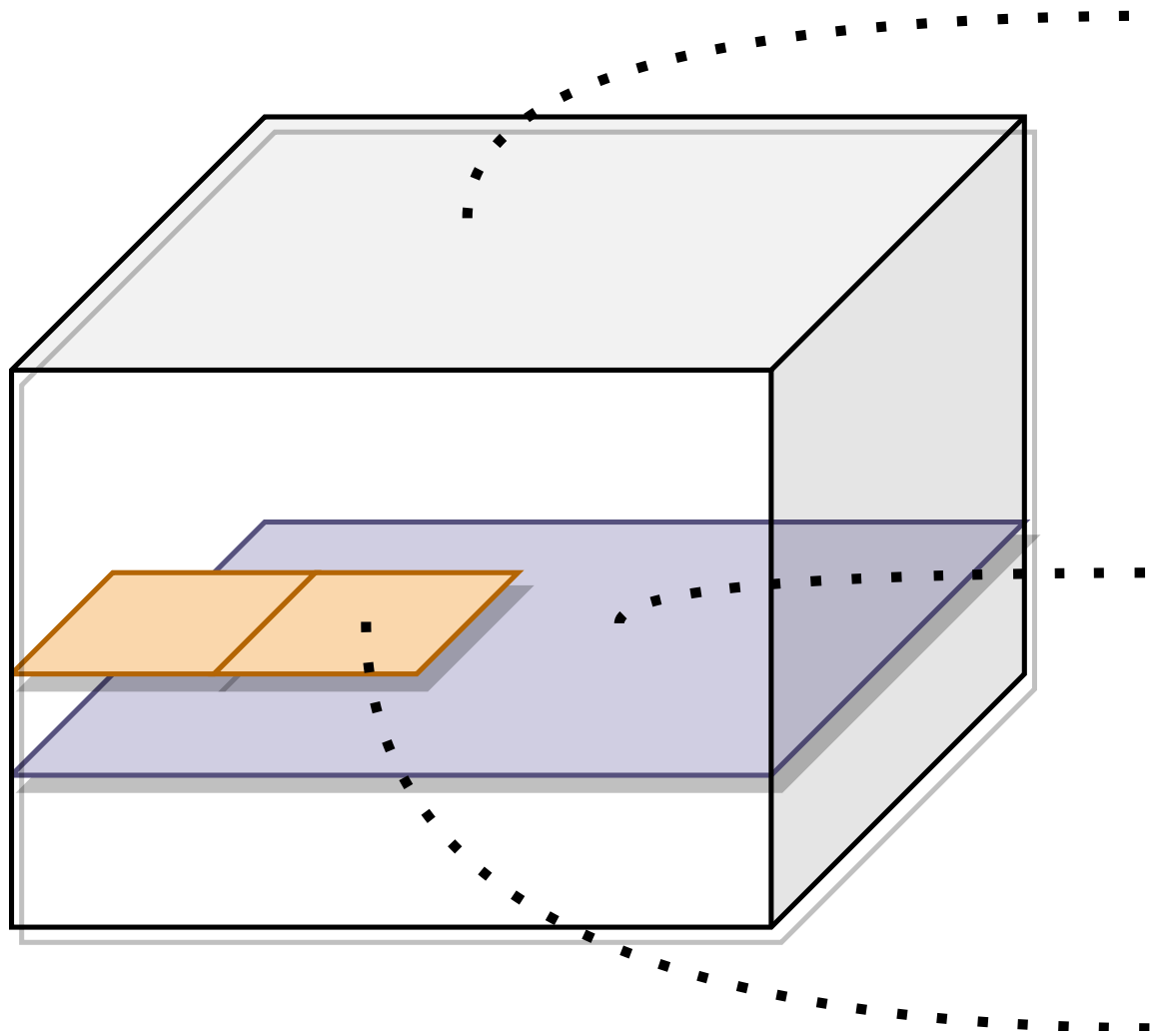
*An object that semantically defines a space*

- ▶ Spatial hierarchy
- ▶ Graph connectivity with other spaces
- ▶ Geocoding
- ▶ GeoJSON compatibility
- ▶ Can be used as a location
- ▶ Can be extended ...





# SymbolicSpace ...



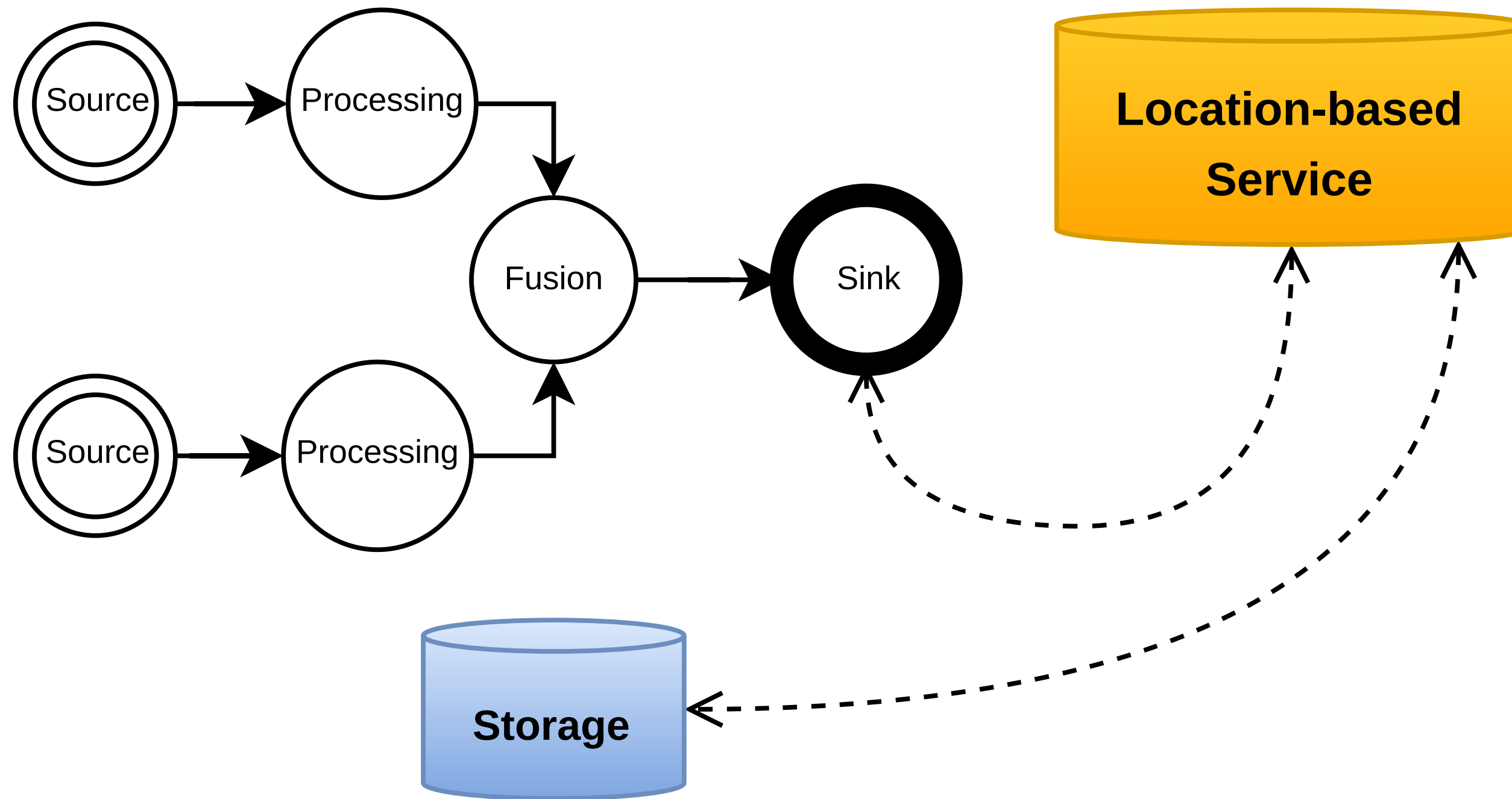
```
const building = new Building("PL9")
  .setBounds({
    topLeft: new GeographicalPosition(
      50.8203,
      4.3922),
    width: 46.275,
    height: 37.27,
    rotation: -34.04
  });

const floor = new Floor("PL9.3")
  .setBuilding(building)
  .setFloorNumber(3);

const office = new Room("PL9.3.58")
  .setFloor(floor)
  .setBounds([
    new Absolute2DPosition(4.75, 31.25),
    new Absolute2DPosition(8.35, 37.02),
  ]);
```

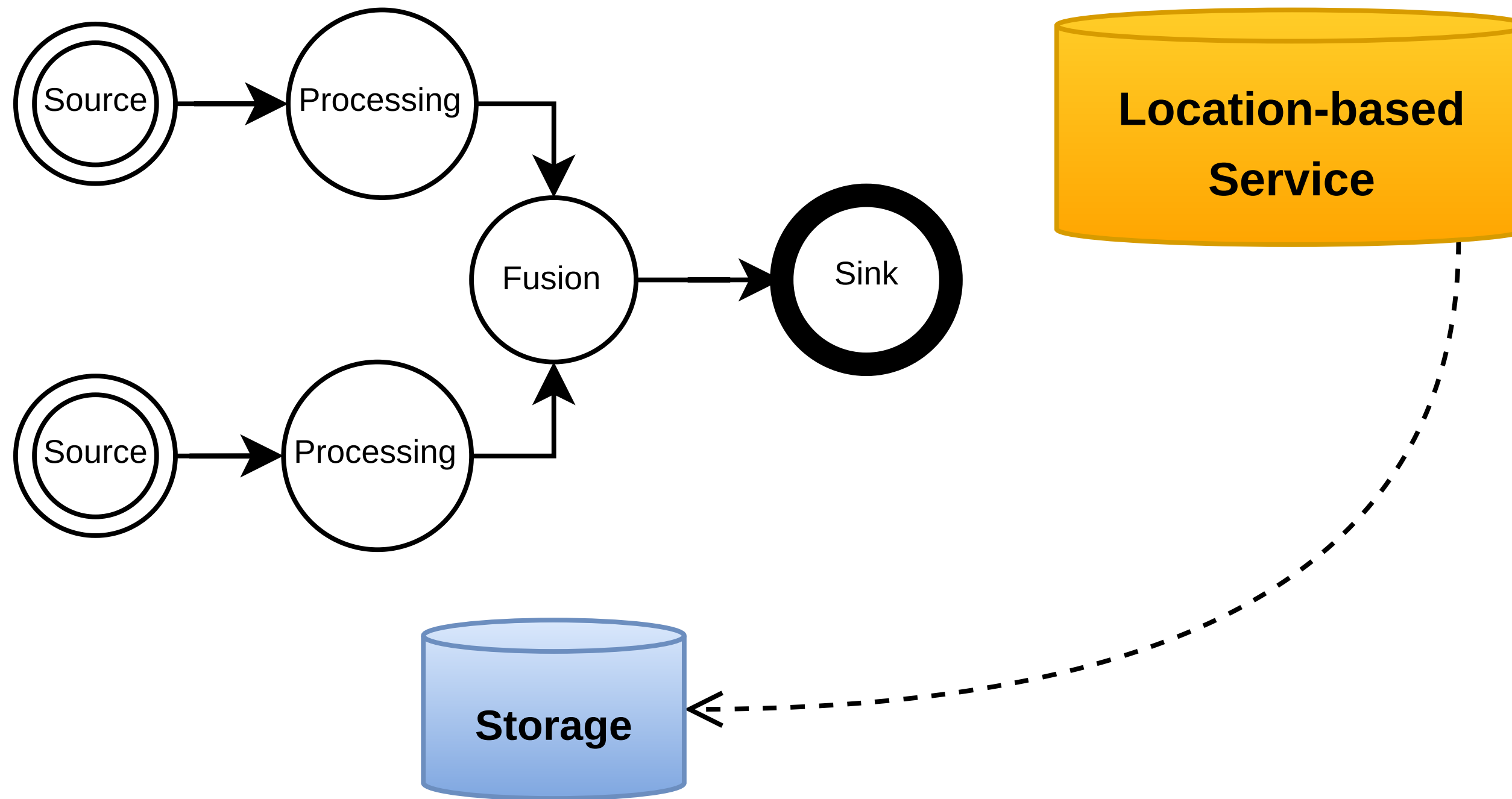
# Location-based Service

`getCurrentPosition("me", ...)`



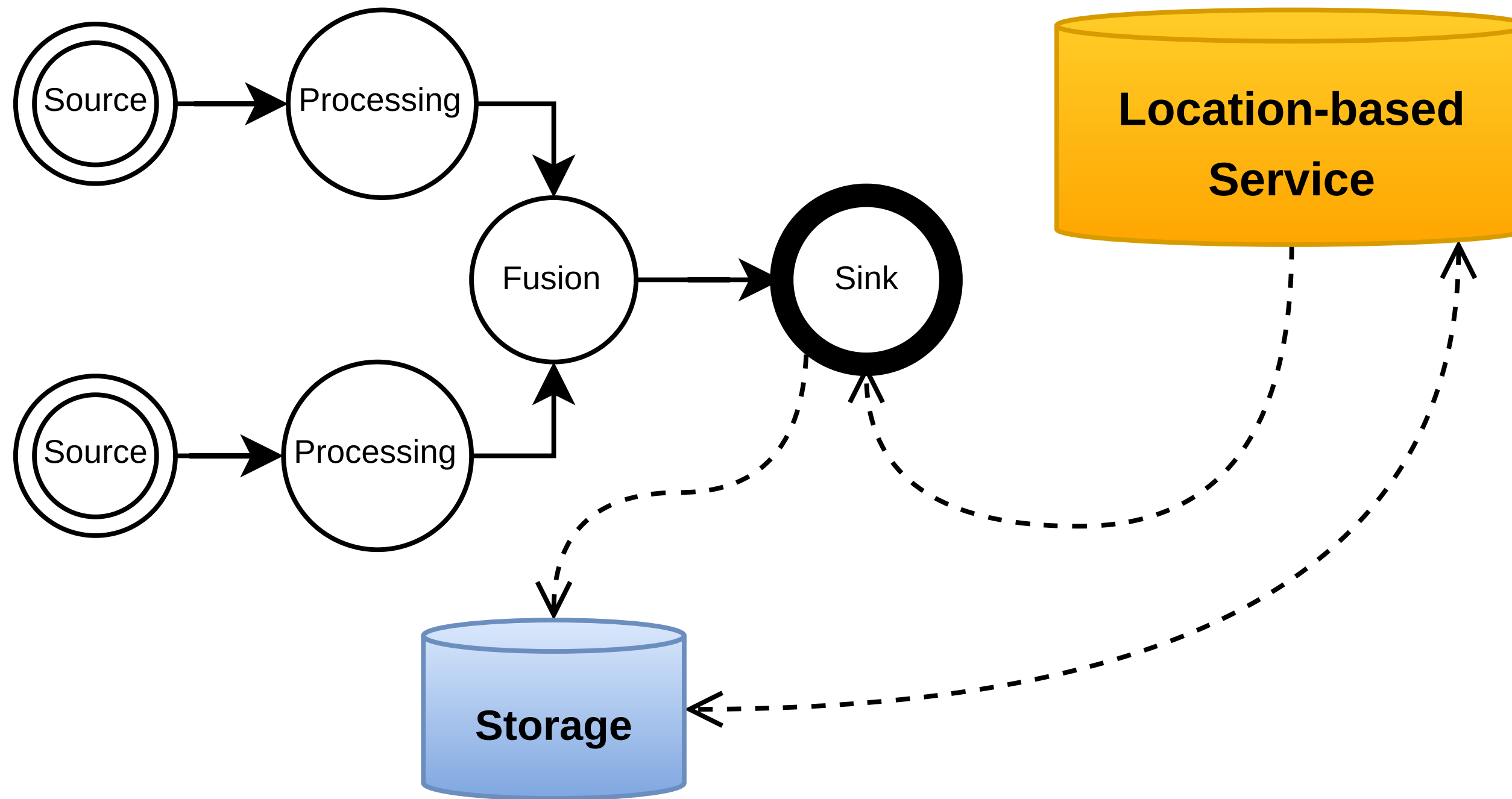
# Location-based Service ...

`setCurrentPosition("me", ...)`



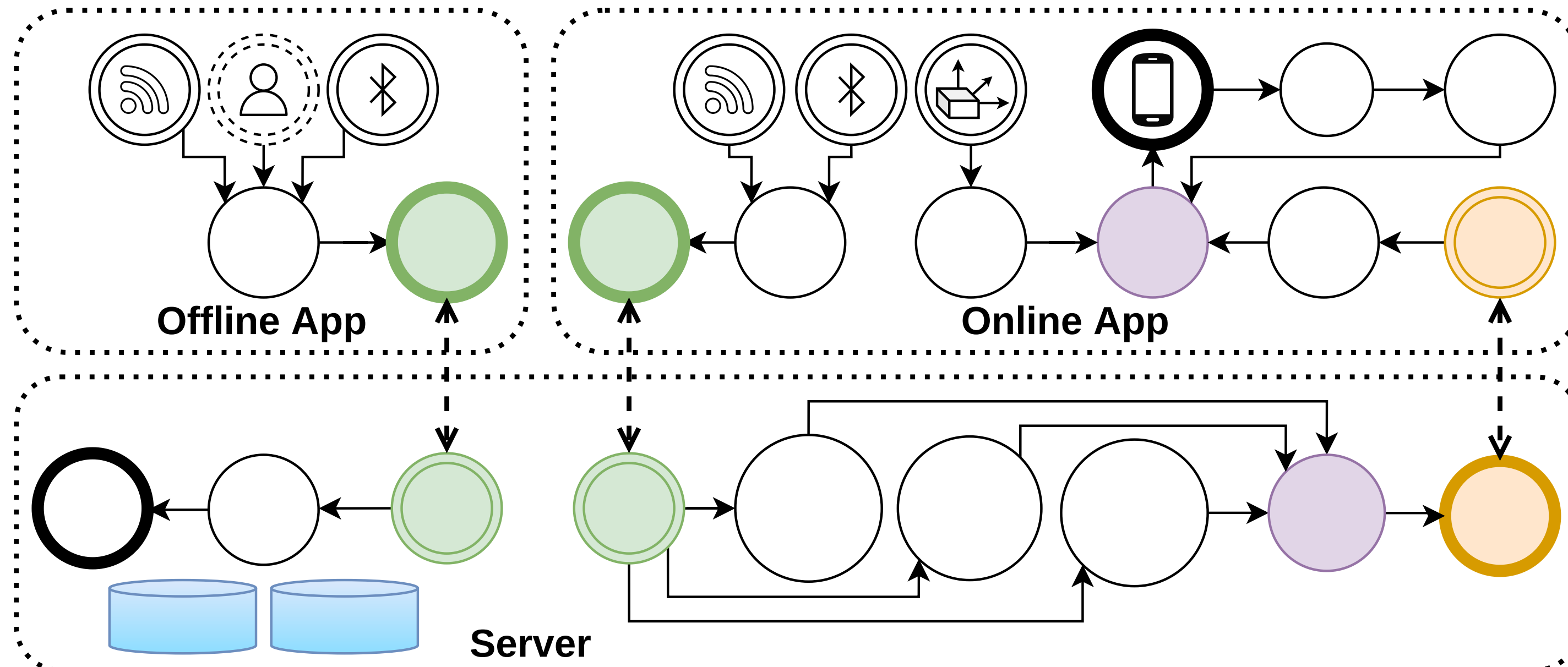
# Location-based Service ...

`watchPosition("me", ...)`

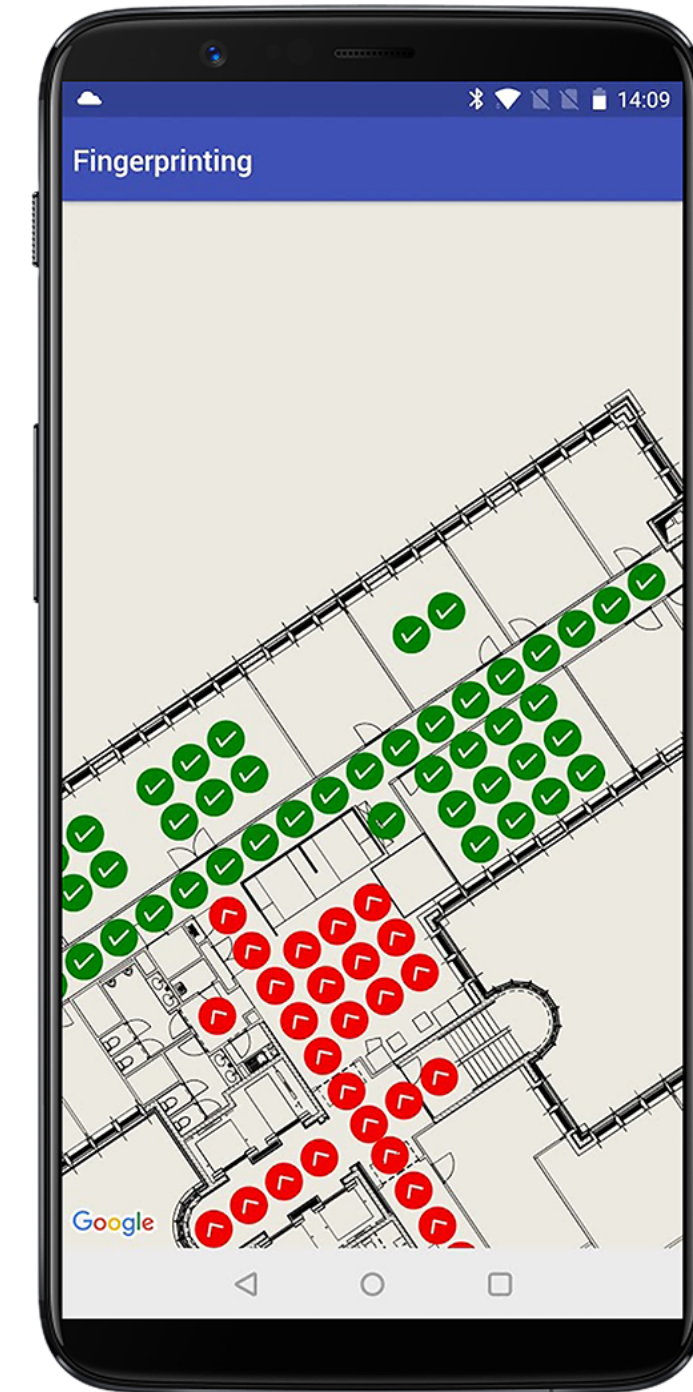
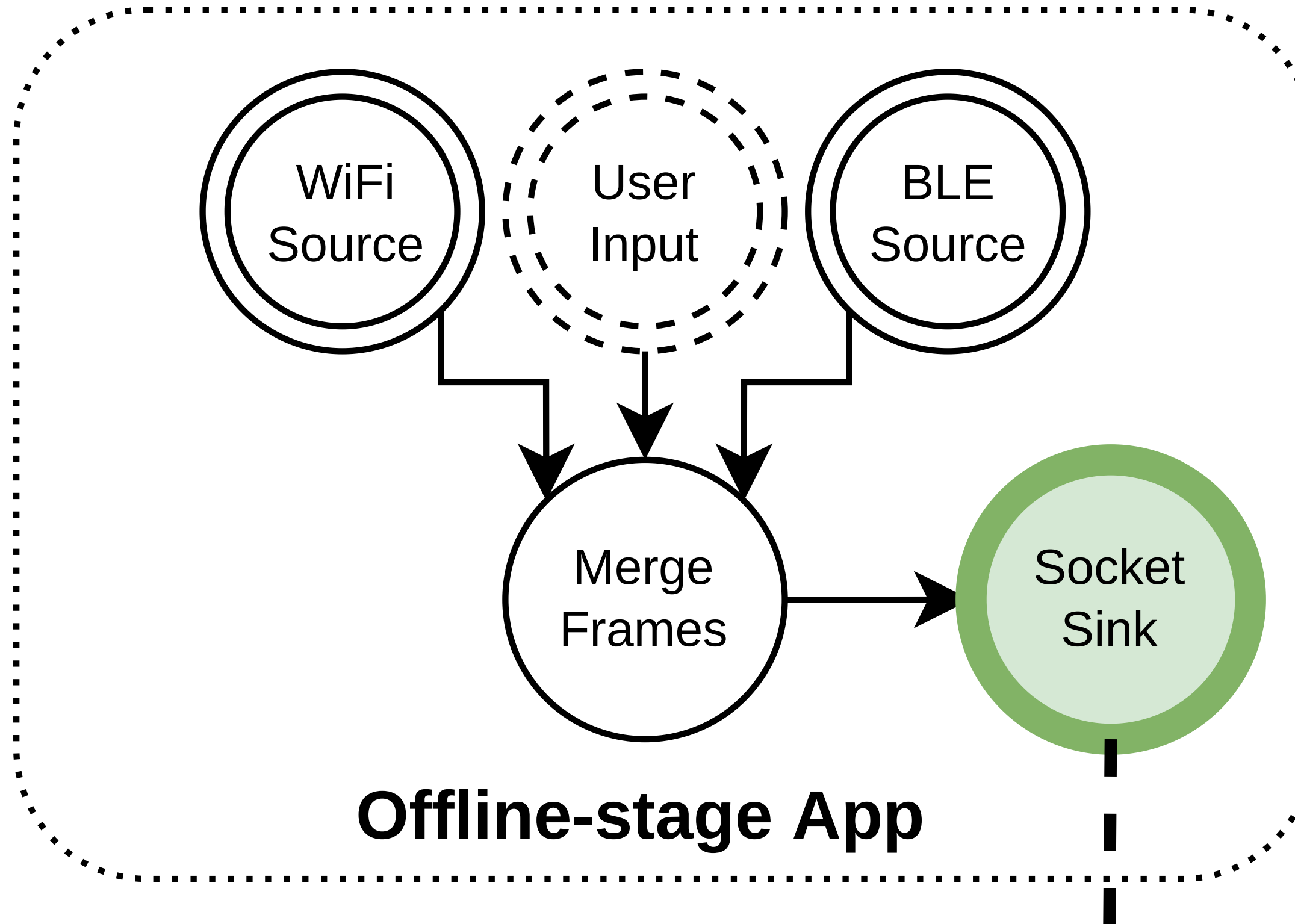


# Demonstration

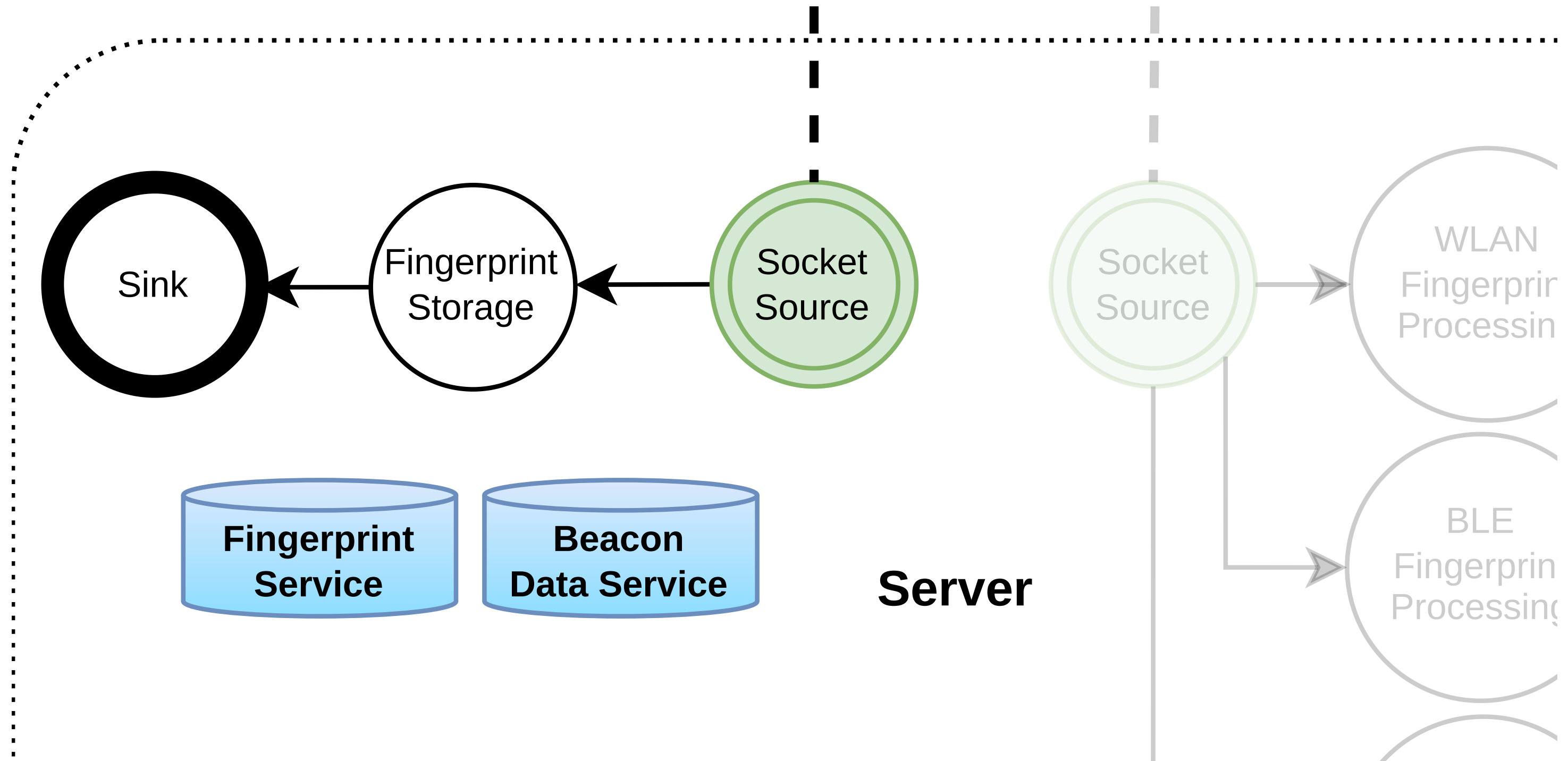
- ▶ Indoor positioning **use case**
- ▶ Use **existing techniques**
- ▶ Validation of **flexibility** and modularity



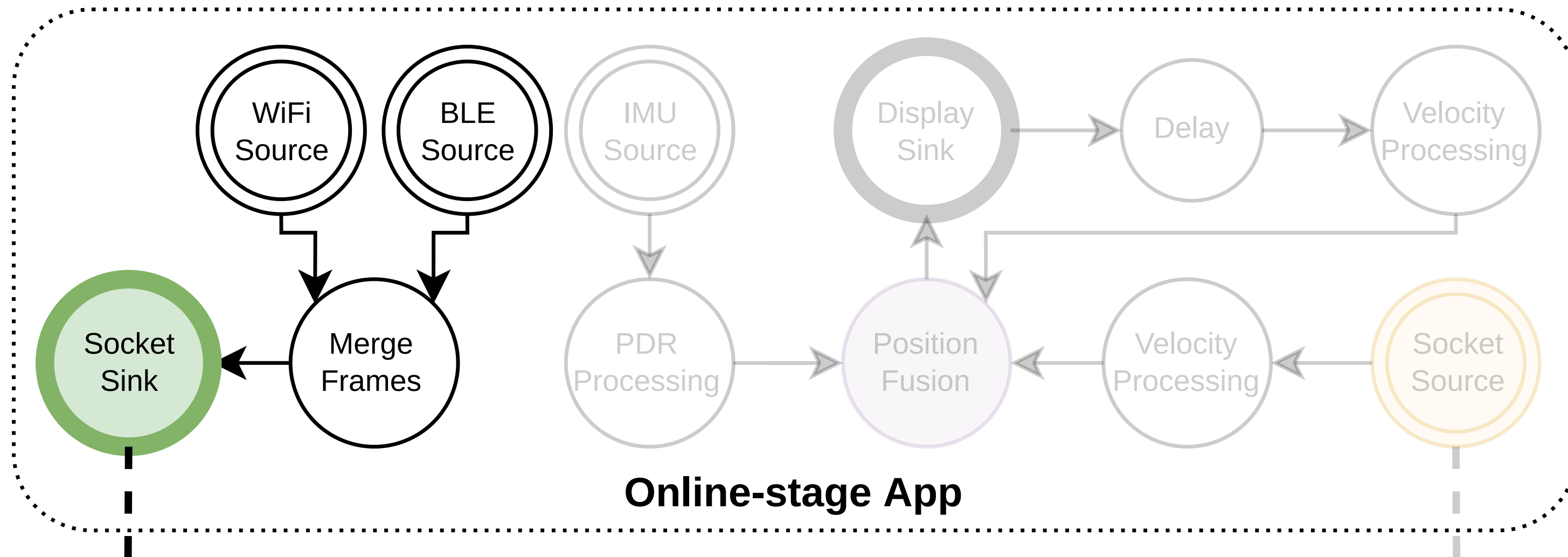
# Positioning Model



# Positioning Model ...

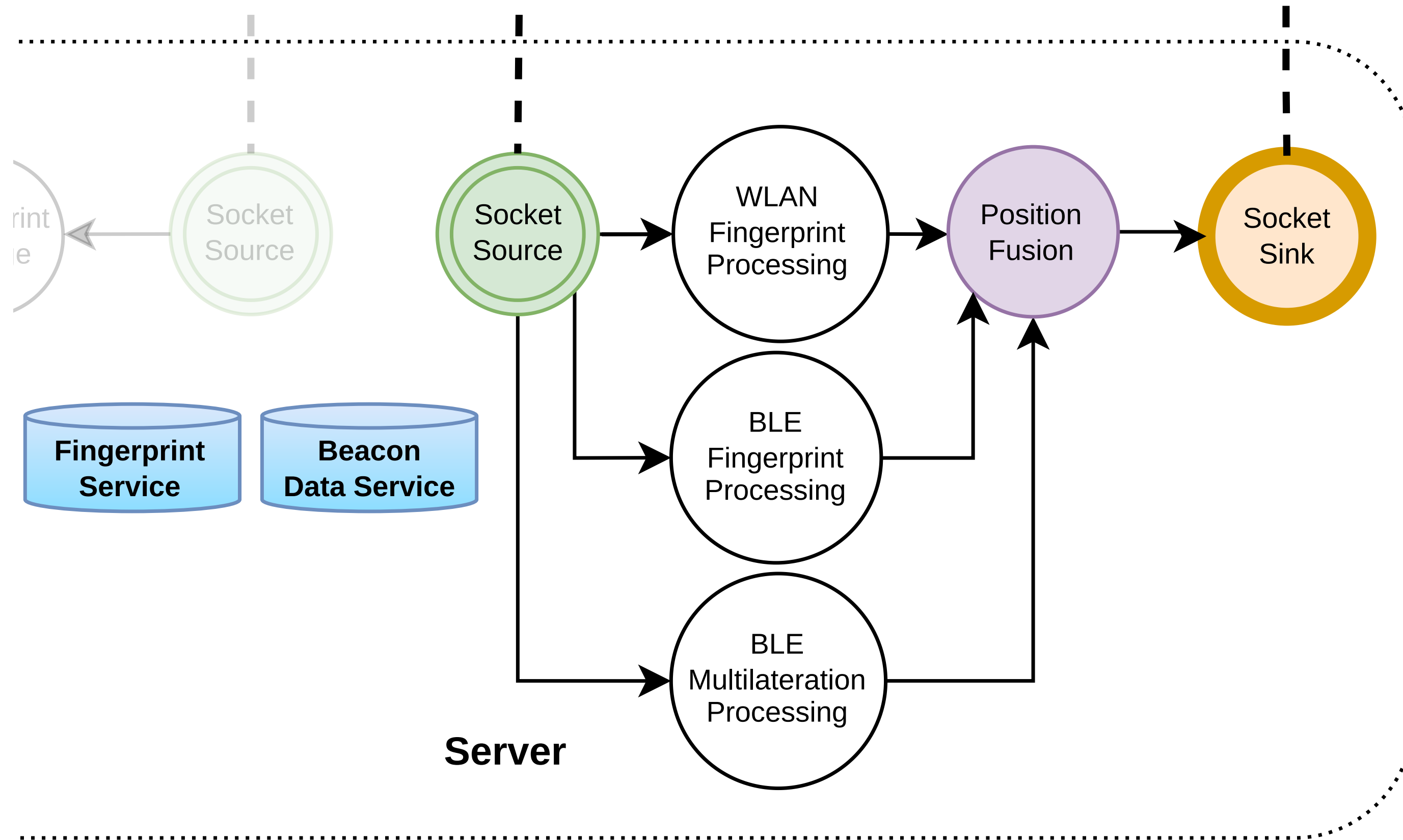


# Positioning Model ...

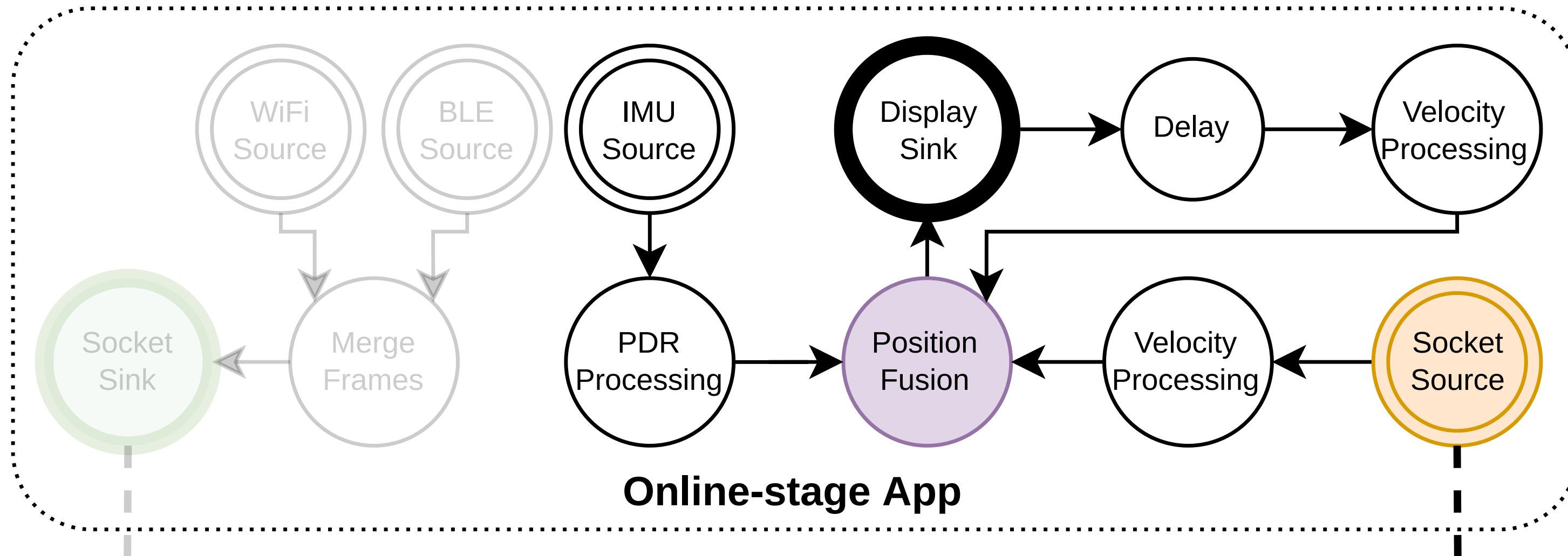




# Positioning Model ...

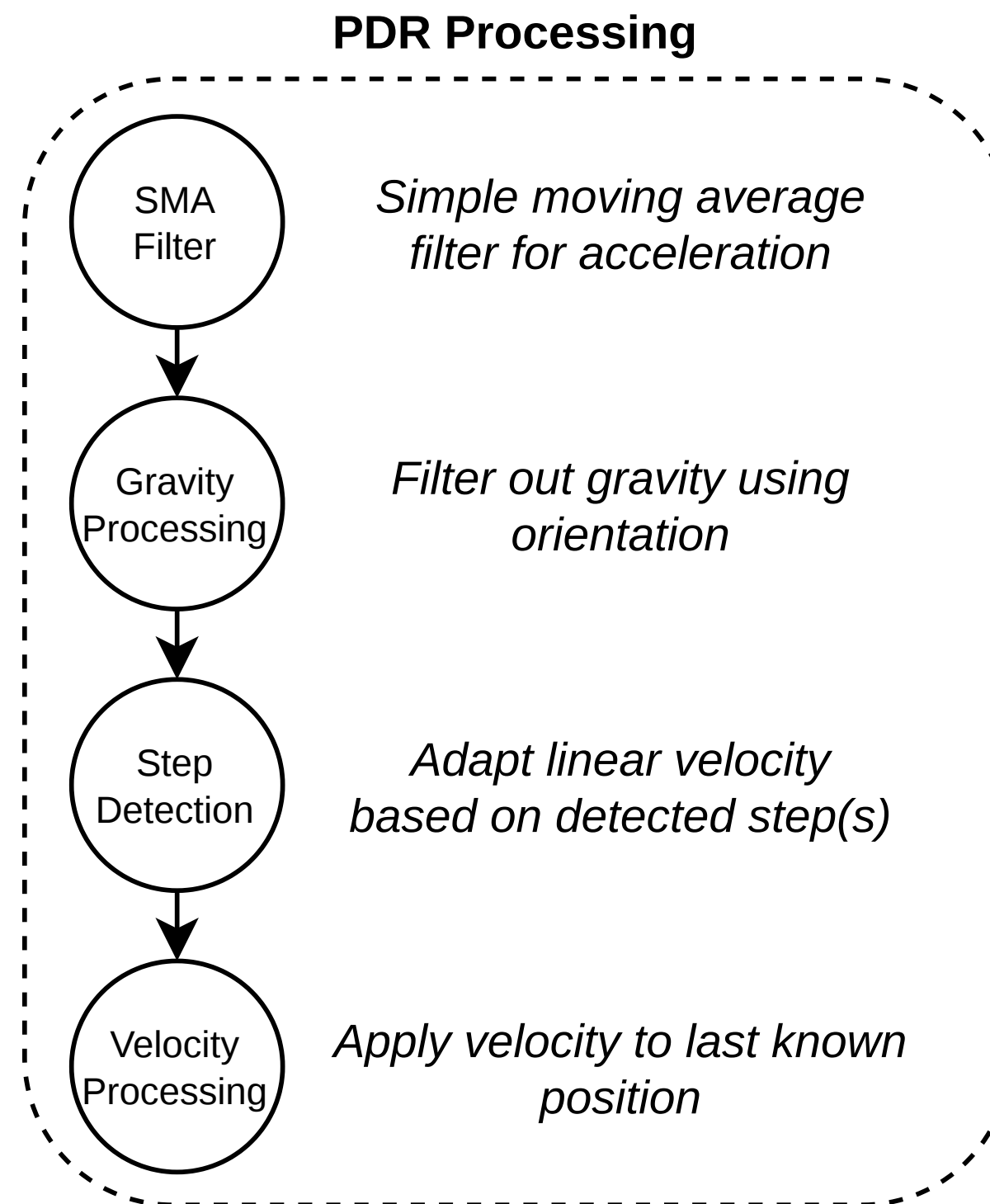


# Positioning Model ...



# Positioning Model

## Online App

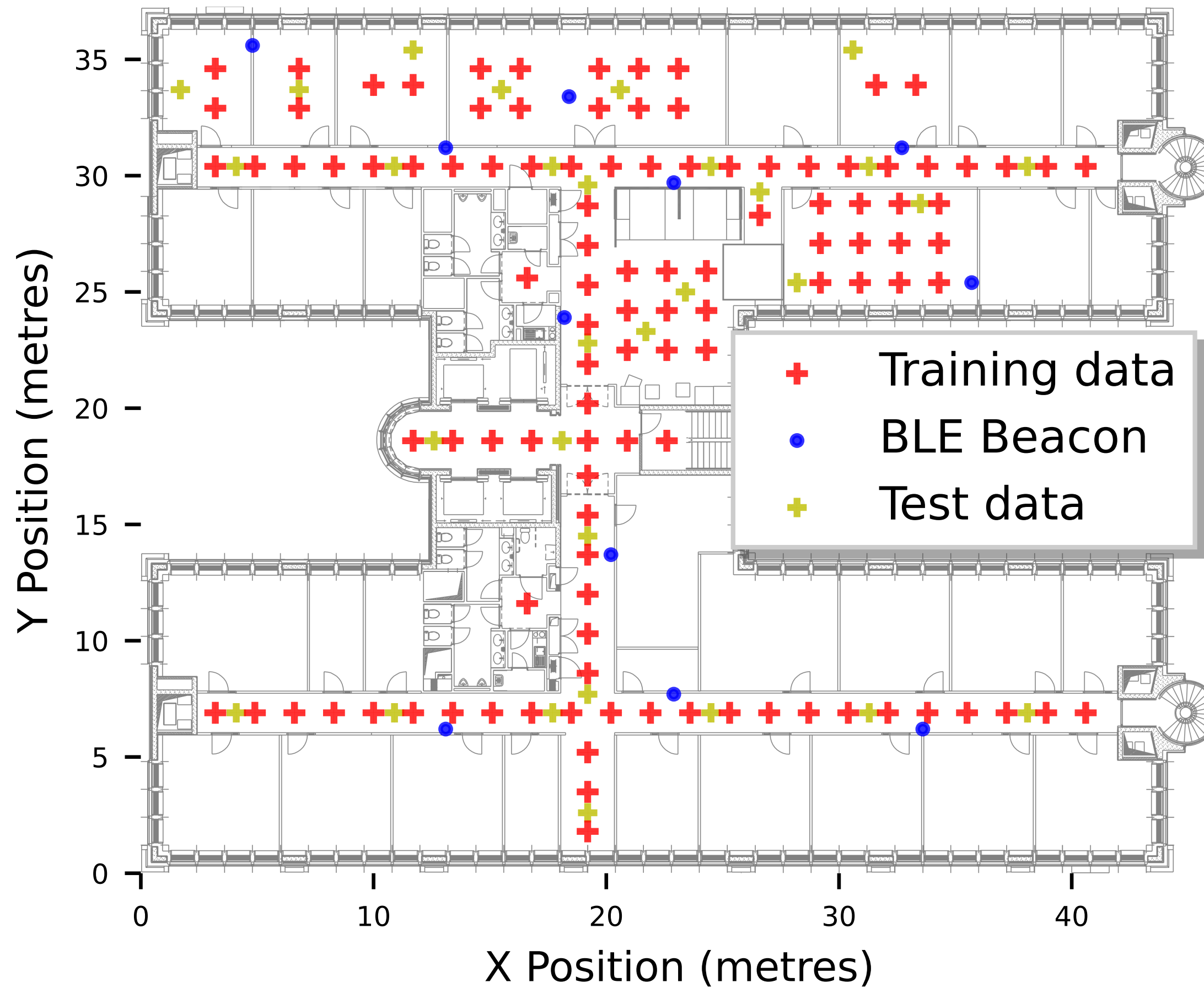


# Positioning Model

## Online App

```
ModelBuilder.create()  
  .addShape(GraphBuilder.create()  
    .from(new IMUSourceNode({  
      source: new DataObject(phoneUID),  
      interval: 20,  
      sensors: [  
        SensorType.ACCELEROMETER,  
        SensorType.ORIENTATION  
      ]  
    })))  
  .via(new SMAFilterNode(  
    frame => [frame, "acceleration"],  
    { taps: 10 }  
  ))  
  .via(new GravityProcessingNode({  
    method: GravityProcessingMethod.ABSOLUTE_ORIENTATION  
  })))
```

# Dataset



# Dataset ...

**Total BLE Beacons: 11**

**Total detected WLAN access points: 220**

**Total stable WLAN access points: 199**

	Training	Test
<b>Datapoints</b>	110	30
<b>Total fingerprints</b>	440	120
<b>Duration</b> (per orientation)	20s	20s
<b>Avg. WLAN Scans</b> (per fingerprint)	6	6
<b>Avg. BLE Advertisements</b> (per fingerprint)	16	15

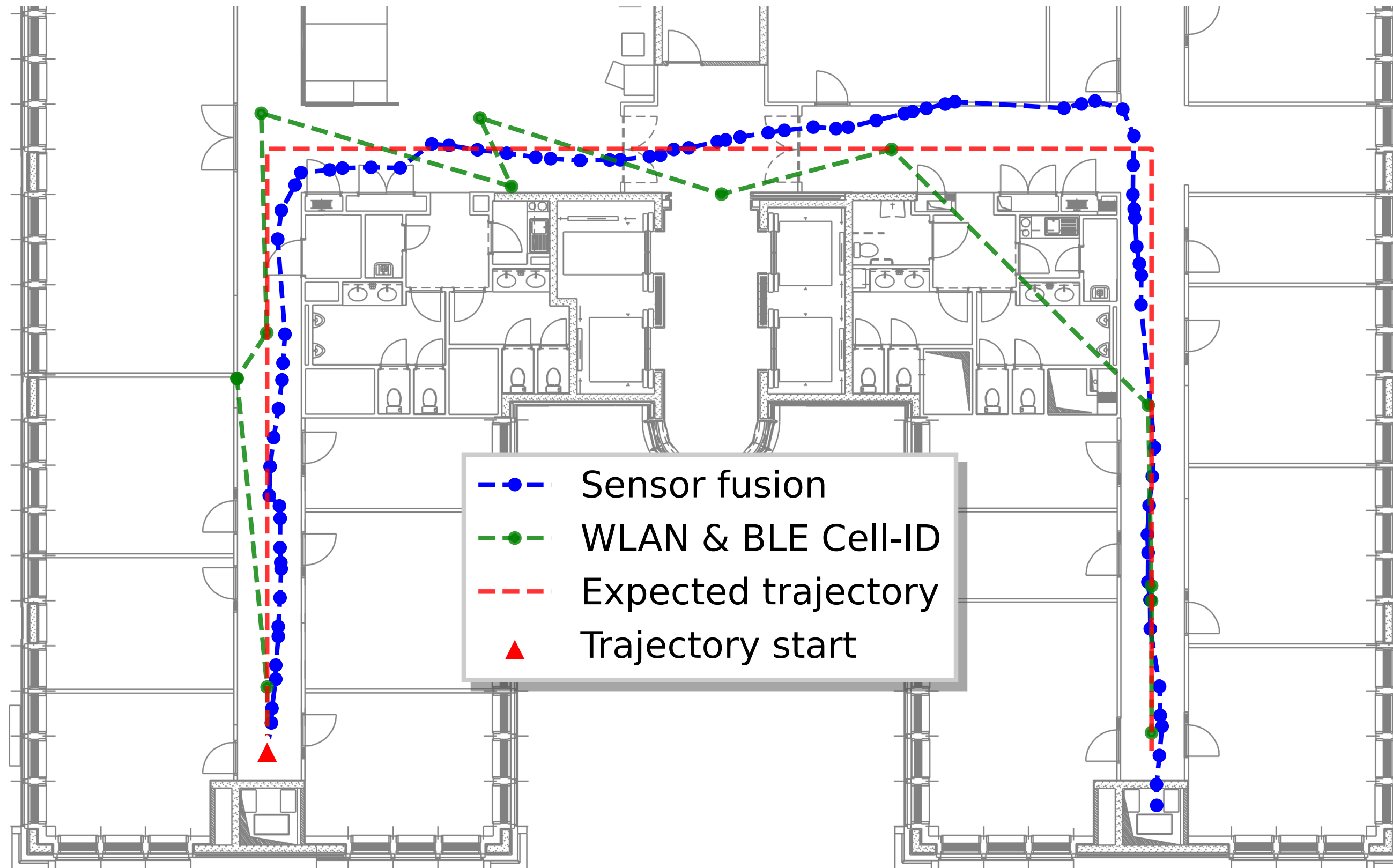
# Validation Results

## Static Positioning

	WLAN	BLE	BLE	Fusion
	fingerprinting	fingerprinting	multilateration	
<i>failed points</i>	0	6	12	0
<i>average error</i>	1.23 m	3.23 m	4.92 m	1.37 m
<i>minimum error</i>	0.01 m	0.17 m	0.74 m	0.01 m
<i>maximum error</i>	4.77 m	15.39 m	19.26 m	9.75 m
<i>hit rate</i>	95.82 %	80.83 %	52.50 %	96.67 %

# Validation Results ...

## Trajectories

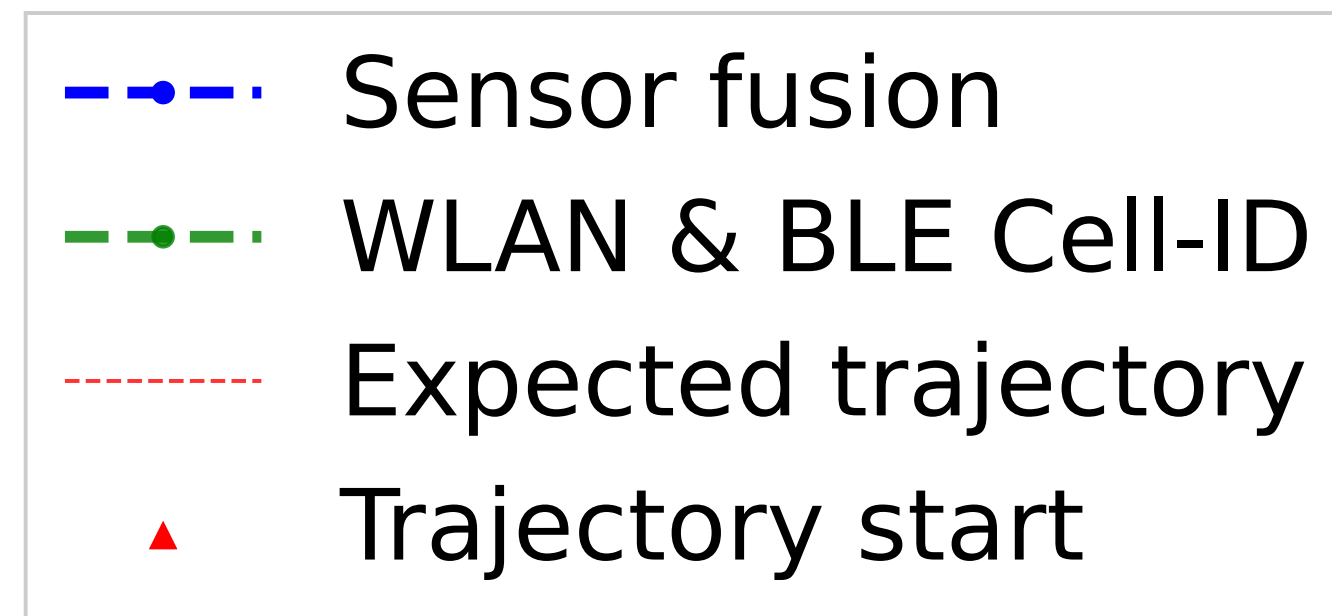
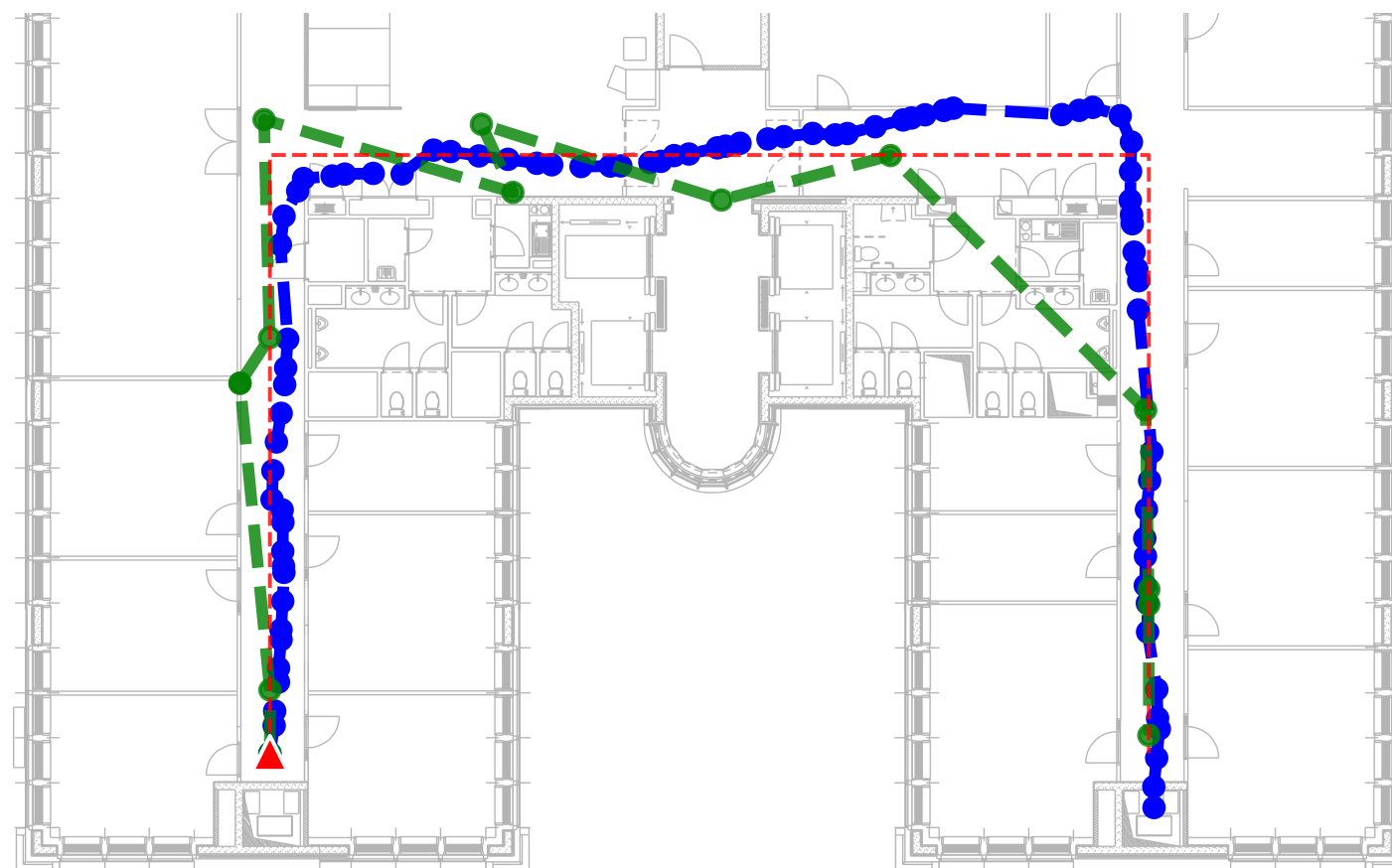




# Validation Results ...

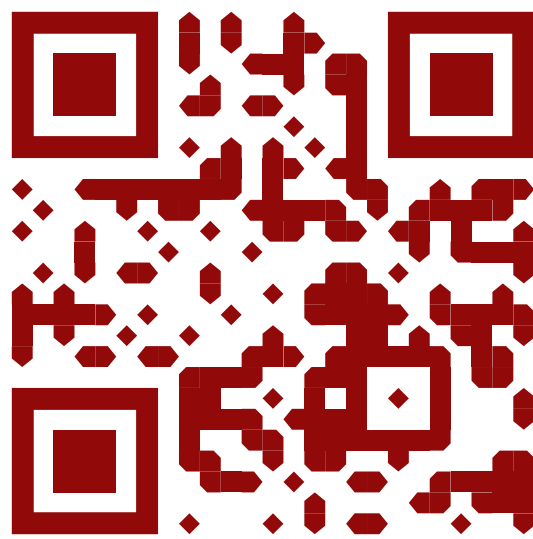
## Trajectories

	WLAN + BLE	WLAN + BLE + IMU
<i>average error</i>	3.28 m	1.26 m
<i>maximum error</i>	9.60 m	3.10 m
<i>average update frequency</i>	3.04 s	0.52 s



# Contributions and Conclusions

- ▶ OpenHPS: **open source** framework for hybrid positioning
  - Aimed towards **developers** and **researchers**
- ▶ **Abstractions** such as location-based services and spaces
- ▶ Validation of an indoor positioning use case
- ▶ Configurable and interchangeable **nodes** and **services**
- ▶ **Public dataset** with multiple orientations



Visit <https://openhps.org> for additional resources, documentation, source code and more!