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# ASSIGNMENT THEME 3

# How are the GPS’s satellites organized? How many they are and what kind of orbits they have?

 GPS is initially planned to accommodate having 24 satellites in 3 circular orbits each consisting 8 satellites. This was latter modified to accommodate 6 planes each hosting 4 satellites. It should be noted that GPS orbits range from 11000 – 12000 miles above the surface of the earth.

These satellites in the orbital system is arranged by considering mathematical models for making sure that each instance and every point at least six satellites are in the line of sight . Each orbit is separated by 60 apart and maintains an inclination of 55Each satellite has as orbital time period of 11 hours and 58 minutes which means every satellite orbits earth twice a day. Satellites in an orbit are placed such a way that they make 30, 120 angular differences between them where Σ of angles make 360 degrees.

Satellite positions are always monitored by US defence agency whose job is correct them for any related errors that creep into and are affecting their orbits. These satellites are tracked from ground by radars for their position , speed and altitude for rectifying the errors.

# How is the trilateration organized in the 3D-space? Why is the fourth satellite needed to specify the location point?

For our discussion , let us consider our receiver has access to 3 satellites A,B,C orbiting at 11000 , 11500, 12000 miles in the space and see how trilateration is deduced.

Considering the satellite A is at 11000 miles in the space , target can be anywhere on the surface of the sphere with a 11000-mile radius.

Knowing target’s location as 11,000 miles from a particular satellite narrows down all the possible locations to just the surface of a sphere that is centered on this satellite .Now distance from another is calculated as 11500 miles from satellite B which essentially forms another sphere. . These two spheres would intersect in a circular fashion. Similarly If you have another satellite at a distance of 12500 miles , we get a third sphere, which intersects with this circle at two points. So by ranging from three satellites we can narrow our position to just two points in space. In these two points one of the points is either too far from Earth and can be rejected without a measurement. For knowing which one to discard we can consider Earth as fourth sphere. Considering this fourth sphere will only intersect with the position on the earth discarding the position in the space.

# Explain picture 2.28 in Bensky’s book. Is there something wrong in that picture?

Yes , Picture 2.28 does not show the 90 phase shift quadrature signal modulated with CA code from L1 carrier is not to be (added ) to in-phase P(Y)Code modulated signal. So in the picture part of summation of CA Code and P(Y) Code is absent before the signal is transmitted via antenna from L1 carrier. Only P(Y) code is transmitted here from L1.

# Why there are two separate codes and frequencies? How they are used?

Satellites in space segment transmit on two different frequencies which are 1,575.42 MHz, and 1,227.6 MHz referred as L1 and L2. Reason of transmitting in two different frequencies is for receivers to accurately calculate speed of propagation of signal in the atmosphere. Signal is transmitted as spread spectrum on two channels with chip rate of 1.023 Mbps on L1 and 10.23 Mbps on L2. Chip rate can be defined as rate of codded bits that are modulated with the data to spread signal bandwidth beyond that required for data alone.

Satellites use sets of orthogonal codes at two chip rates for code division multiple access so that transmissions on same frequency does not interfere.

There are two different types of codes for two different types of services i.e standard service and precision service. The 1.023 Mbps code is called statadard or coarse acquisition code (C/A-code). CA code has a time period of 1 millisec.This is most commonly used all GPS receivers and provides less accurate positioning information. Other 10.23 Mbps code is called Precision code or P-Code with a period of one week.

Y-Code is an encrypted P-Code ,which is primarily used for defense purposes. Usually US and NATO allies have access to the encrypted keys and therefore take advantage of this high precession and more accurate positioning systems which is possible via higher code rate and greater bandwidth. Navigational data that receiver needs for calculating position is transmitted at 50 bps and is modulated on both CA and P-Codes.

# How is the synchronization between satellites and receivers achieved? What function does the CDMA code have in this operation?

In order to measure the time of flight , clocks in receiver and transmitter has to be synchronized. Synchronization between satellites and GPS receivers is achieved by signal correlation which is essentially a mechanism for delaying the reference code at the receiver end. Receiver has the ability to slide the receivers spreading code in relation to received code from satellite in an effort to make them in line.

Reference or replica code is generated in the receivers at the a start time that is synchronized with clock of receiver. We know that there can be definite time delay in signal propagation and received code will be certain phase difference compared against the generated receiver code. It is necessary to change this generated signal phase and line up with the received code signal . which is delayed due to transmission time. So there is a certain delay between the received code and reference code in the receiver. Synchronization is attained by receiver slowing down the reference code to allow to lineup with the received code.

Receiver is able to measure who much of phase shift there was from the reference in the receiver until the phase shift two signals are lined up.

# How does the receiver know where the satellite is?

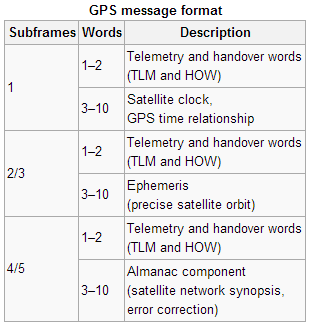
Satellites provide embedded information needed for receivers in their transmissions as data frames . The navigation message itself is constructed from a 1,500 bit frame, which is divided into five subframes of 300 bits each and transmitted at 50 bit/s. Each subframe, therefore, requires 6 seconds to transmit. Each subframe has the GPS time

Each sub-frame begins with telemetry word and handover node where telemetry contains synchronization preamble and handover gives the exact transmission time of satellite when the signal is transmitted.

Sub frame 1 contains the GPS date (week number) and information to correct the satellite's time to GPS time, plus satellite status and health whether the satellite can be used or not.

Sub frames 2 and 3 together contain the transmitting satellite's ephemeris data. This data describes the location of the satellite in its orbit. **Satellites coordinates are calculated as function of time using the ephemeris data from sub frames 2 and 3**.

Sub frames 4 and 5 contain components of the almanac. Each frame contains only 1/25th of the total almanac; a receiver must process 25 whole frames worth of data to retrieve the entire 15,000 bit almanac message. At this rate, 12.5 minutes are required to receive the entire almanac from a single satellite.



The almanac consists of coarse orbit and status information for each satellite in the constellation. Almanac assists receivers in the acquisition of satellites at power-up by allowing the receiver to generate a list of visible satellites based on stored position and time, while an ephemeris from each satellite is needed to compute position fixes using that satellite

The second purpose is for relating time derived from the GPS (called GPS time) to the international time standard of utc.

Almanac contains additional data required for measurement accuracy , specifically a correction factor for adjusting the propagation time of signal which changes slightly according to the parameters of ionsphere. It also allows receiver to convert from the satellite time to GPS time. From almanac data receiver can determine what satellites are in the view of its location.

Almanac data can be used only for initial satellite acquisition by the receiver.

We know that GPS receivers does a signal correlation job using the replica of code transmitter by the each satellite. In order to get the above information from enough satellites, receivers should do this correlation job on all these satellites most often done in paralle using digital tracking mechanism rather that in series.

Sequential steps on how GPS receivers calculate and know their geographical position .

* GPS receivers lock on to the satellites means locking or lining up with the satellites code with the replica code in the receivers.
* Calculate the pseudo range which is the time difference between received signal and transmitted time multiplied by the speed of propagation.
* Fetch the satellite position coordinates from the navigation message.
* Receiver position can be calculated once it knows the satellite positions.
* As final step, the receiver position can be used to calculate geographic position i,e Latitude , longitude and altitude.

# Explain how the following errors are originated and how at least part of them can be corrected in GPS system:

# Satellite clock errors

# Satellite orbit errors

# Ionosphere and troposphere errors

# Multipath errors

# Dilution of precision

**Orbit errors:**

Satellite Orbit errors are also referred as ephemeris errors. Ephemeris data is part of navigation message (sub-frame 2 &3) from the satellites. This data describes satellites position in the orbit. Ephemeris data is transmitted every 30 seconds and this information may be couple of hours old. Ephemeris errors may be result of solar radiation in the outer atmosphere. Receivers are enabled with almanac of this data for all the satellites and they update the data when ever new data is available.

It is also feasible to put ephemeris data on web where receivers connect to and load the updated information.

**Satellite Clock Errors:**

Satellites have atomic clocks and can experience noise and clock drifts errors. Navigation messages contain this clock error correction information as part of sub-frame 1 and based on the accuracy of atomic clock.

For precise positioning , effects of clock drifts can be overcome by using differential GPS which is using simultaneously using two or more receivers at multiple survey points.

**Ionosphere and troposphere errors:**

Errors can creep in while GPS signal passes through the Earth’s outer and inner atmosphere.

These errors can pose a significant challenge for maintaining position accuracy.

Errors caused by ionosphere is due to presence of ionized particles in the outer space.

Ionospheric effects are smallest when satellite is right overhead and maximum when satellites are nearer the horizon. Ionospheric delay of microwave signal depends on its frequency due to signal dispersion in the space .

Ionosphere errors can be calculated from measurement of delays for two or more frequency bands , allowing delays at other frequencies to be estimated. The effects of ionosphere generally change slowly and can be averaged out in time. Once the receiver's approximate location is known, a mathematical model can be used to estimate and compensate for these errors.

Humidity and water vapor are the major contributors to tropospheric errors , they vary with temperature and pressure.  This effect is more localized and changes more quickly than ionospheric effects, and is not frequency dependent. This makes precise measurement and compensation of humidity errors more difficult than ionospheric effect.

GPS receivers apply mathematical models to computes this error , either by applying a function regression or correlating margin of atmospheric error to ambient pressure using a barometric altimeter.

**Multipath errors**

In a real world scenario , Signal take multiple paths to reach any receiver because they are bound to bounce on other objects in the environment before they reach the receiver.

However the signal that reaches first is the one that travelled direct path and the delayed ones are from reflections.

Reflected signals can be strong enough to induce errors and cause faulty measurements .

Advanced GPS receivers use various signal processing techniques to nullify the reflected signal and use the direct ones.

**Dilution of precision**

Dilution of precision (DOP) or geometric dilution of precision is the additional multiplicative effect of navigational satellite geometry on positional measurement position. Primary idea is how the errors in the measurement will effect the final state measurement. When visible navigation satellites are close together in the sky, the geometry is said to be weak and the DOP value is high; when far apart, the geometry is strong and the DOP value is low.

The effect of geometry of the satellites on position error is called geometric dilution of precision and it is roughly interpreted as ratio of position error to the range error. If satellites overlap at right angles, the greatest extent of the overlap is much smaller than if they overlap in near parallel. Thus a low DOP value represents a better positional precision due to the wider angular separation between the satellites used to calculate a unit's position. Other factors that can increase the effective DOP are obstructions such as nearby mountains or buildings.

# Explain the main principle of differential GPS (DGPS).

Differential GPS is improved version of GPS in terms of positional accuracy.

GPS accuracy is approximately around 15 meter and differential GPS can bring around 10 meter accuracy. Differential GPS involves the cooperation of two receivers, one stationary and another roving around making position measurements.

The stationary receiver calculates the satellite measurements into a solid local reference.

Differential GPS uses a network of fixed, ground-based reference stations to broadcast the difference between the positions indicated by the satellite systems and the known fixed positions. These stations broadcast the difference between the measured satellite pseudoranges and actual internally computed pseudoranges, and receiver stations may correct their pseudoranges by the same amount.

The baselines represent a three-dimensional line drawn between the two points occupied by each pair of GPS antennas. The post-processed measurements allow more precise positioning, because most GPS errors affect each receiver nearly equally, and therefore can be cancelled out in the calculations.

This reference station receives the same GPS signals as the mobile or any GPS receiver. This reference station having pre-known its coordinates , tries to calculate the position from the GPS signals and determines the deviation from the exact against calculated values. The difference between the actual fixed values and the calculated values from the GPS signal is an "error correction" factor. The receiver then transmits this error information to the other receivers to correct their measurements.

Differential GPS can also aid in correcting errors that are common to both the reference receiver and the revolving receiver.

Post-processing is used in Differential GPS to obtain precise positions of unknown points by relating them to known points such as survey markets. The GPS measurements are usually stored in memory in the GPS receivers, and are subsequently transferred to a computer running the GPS post-processing software. The software computes baseline data using simultaneous measurement data from two or more GPS receivers.

# How do the EGNOS and WAAS systems complement the GPS system?

Both EGNOS and WAAS are satellite based augmentation systems which work on network of ground based reference stations which can measure the small variations in the GPS satellite signals . These measurements are routed to master stations which queue the correction messages and send these to geostationary satellites in timely manner. These satellites broadcast the corrections messages back to earth where GPS receivers can use this information to improve the accuracy.

EGNOS is a European space agency’s version of satellite based augmentation positioning system. EGNOS suppliments the GPS and GLONASS by reporting on accuracy and reliability of the positioning data. EGNOS has started operations in 2005 with an accuracy of 2 meters.

WAAS, is Wide area augmentation service developed by Fedaral Avation Adminstration from United states and is active in North America .Accuracy of the WAAS is around 7 meters around 95% of the time.

Similar to WAAS ,EGNOS is mostly designed for aviation users which enjoy unperturbed reception of direct signals from satellites up to very high latitudes. The use of EGNOS on the ground, especially in urban areas.

# Explain the idea of A-GPS. (This will be studied further in mobile positioning’s theme)

AGPS(assisted GPS) is a mechanism to improve startup performance for GPS based positioning systems. Approximately 30 to 40 seconds is needed for any traditional GPS receivers to lock on to the GPS satellites which is referred as time-to-first-fix.

Downloading ephemeris and almanac information directly from satellites typically takes a long time by GPS receives when operating at satellites signal rate of 50 bits per second. This problem will be magnified signals are lost during the initial first-fix phase.

Traditional GPS receivers uses radio signal from the satellites. But devices can take the advantage of A-GPS technology which uses cellular air interface resources to use the satellites in relatively poor satellite signal conditions .

This A-GPS feature is extemly usefull at indoor locations where GPS signals are difficult to obtain. As the A-GPS uses cellular network , this feature is highly dependent on network and requires support form the operator providers. A-GPS enabled devices are connected via data connection to internet to fetch the AGPS information.

Assisted GPS can be categorized as Mobile station based and Mobile station assisted.

Mobile Station Based (MSB): Mobile station based AGPS technology mandates GPS receivers to acquire and lock on satellites (by fetching ephemeris , reference postion and time) from the designated A-GPS servers in the network . This would help GPS receivers to lock to the satellites with the least possible time-to-first fix values. Once the GPS receivers are locked on to satellites, they carry GPS operations by themselves.

Mobile station assisted (MSA) : Under the MSA based solution ,Most of the job is carried out by the service provider or operator. Here GPS receives gets the needed information like assistance , reference time from the service provider. Service provider also fetches the almanac information from the GPS satellites and relays them to its AGPS servers in its own system. Now A-GPS system has the almanc and information received from devices calculates the positioning information and sends it to the A-GOS devices.

# Explain the idea and main principles of pseudolite systems.

Pseudolite is an synonym to “Pseudo –Satellite” which means they behave and perform functions similar to satellite systems. Pseudolites systems can be considered as alternate ground based GPS systems. Pseodolotes operate on transceivers whose signal range depends on the power availability .

This kind of system is more useful in places where GPS signal cannot reach or jammed on purpose. Pseudolite systems find their way mostly in precision approach landing systems for aircraft, accurate tracking of transponders and at indoor positioning systems.

# What are the main differences and similarities between Glonass, Galileo and GPS. Make a table including the most important features.

Some of the important characteristics of positions systems to be considered are Number of satellites used , Orbial panes , Orbital pane inclination angles , Orbital radius , Timeperiod ,accuracy , Encoding technology, Modulation , operation bands etc…

All the three major positioning systems (Russian GLONASS , European Galileo , GPS) come with different values of the above parameters . Parameters like number of orbits and number of satellites in a single orbit play a crucial role in defining the accuracy of positioning systems. GPS boosts of 6 where as GLONASS and Galileo has 3 .GLONASS is more accuracy levels in northern part of globe and GPS wins over the rest. More differences can be found in below tables.

|  |  |  |  |
| --- | --- | --- | --- |
|  | **GPS** | **GLONASS** | **Galileo** |
| Number of satellites | 32 | 24 | 27 + 3 |
| Number of Orbit planes | 6 | 3 | 3 |
| plane inclination | 55 | 64.8 | 56 |
| Orbital radius (in KM) | 26650 | 14000 | 23200 |
| Time Period (HH:MM) | 12:00 | 11.15 | |

**Technology table for GPS /GLONASS/GALILEO positioning systems**

|  |  |  |  |
| --- | --- | --- | --- |
|  | **GPS** | **GLONASS** | **Galileo** |
| Encoding Scheme | CDMA | FDMA CDMA | CDMA |
| Modulation Technique used | BOC, BPSK | | BOC, BPSK |
| Data rate(Civilian purpose) | 50 bps, up to 100 sps | 50 bps | 50-1000 bps, up to 1000sps |
| Error rate civilian band) | 5 – 20 m | 50 – 70 m | Claimed 1m |
| Operational bands | L1, L2, L5 | L1, L2, L3, L5 | E1, E5, E6 |

# What is the situation of Glonass and Galileo today? Are they functioning completely?

In 2010, **GLONASS** had achieved 100% coverage area of Russia. After an year roughly ( October 2011) the full orbital constellation of 24 satellites was restored enabling full global coverage.

 The GLONASS satellites have undergone several upgrades, with the latest version being GLONASS-K.

**Galileo** is a European varient of navigation system built by the EU countries and European space agency. Idea behind building Galileo is to provide a high-precision positioning system for EU countries to can rely making them self dependent. Otherwise they are forced to use Russian GLONASS or GPS.

Two satellites were launched by October 2011 other two followed after an year (October 2012), making it possible to test Galileo system partly to certain extent .

Actual plan is to have fully working Galileo systems comprising of 30 satellite constellation of out of which 27 are operational and the rest three are spares by end of 2019.

# References:

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