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## GENIVI Alliance

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GENIVI Document LBS00001

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EnhancedPositionService

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Component Specification

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Draft Version 3.0.0

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19-Jan-2015

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**Abstract:**

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This document provides the Component Specification for the EnhancedPositionService

12

**Keywords:**

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

14

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## 1 Revision History

2 The following table shows the revision history for this document.

### 3 Document revision history

<b>Date</b>	<b>Version</b>	<b>Author</b>	<b>Description</b>
10-Dec-2014	3.0.0	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-Dec-2015	3.0.0	Helmut Schmidt Continental Automotive GmbH	Update text according remaining review comments

4

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# 1 Introduction

## 2 1.1 System Overview

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

## 5 1.2 Component Overview

6 The EnhancedPositionService is a software component of the above mentioned GENIVI Software Platform that  
7 offers positioning information to client applications.  
8

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

## 13 1.3 Document Overview

14 This document describes the architecture and the interface of the GENIVI EnhancedPositionService.  
15

## 1   **2   References**

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

- 7       [1] “GENIVI GNSSService – Component Specification” -  
8       <http://git.projects.genivi.org/?p=lbs/positioning.git;a=tree;f=gNSS-service/doc>  
9       [2] “GENIVI SensorsService – Component Specification” –  
10      <http://git.projects.genivi.org/?p=lbs/positioning.git;a=tree;f=sensors-service/doc>  
11      [3] GENIVI UML Model - <https://svn.genivi.org/uml-model/genivi/trunk>

### 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	<p>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.</p> <p>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.</p>

**Table 1 – Acronym and Term Definitions**

## 1 **4 Requirements**

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



## 1 **5 Constraints and Assumptions**

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

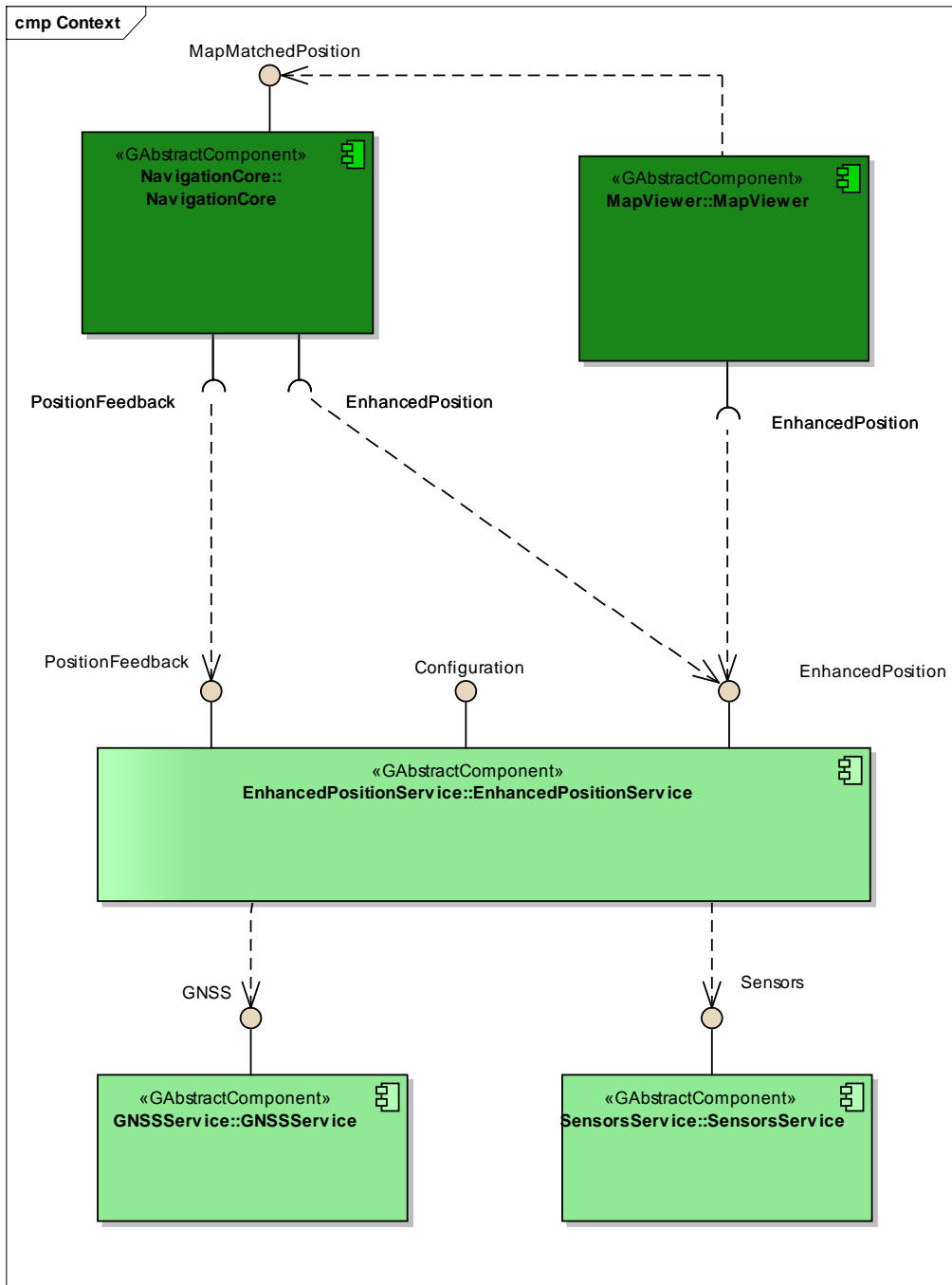
# 6 Architecture

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)

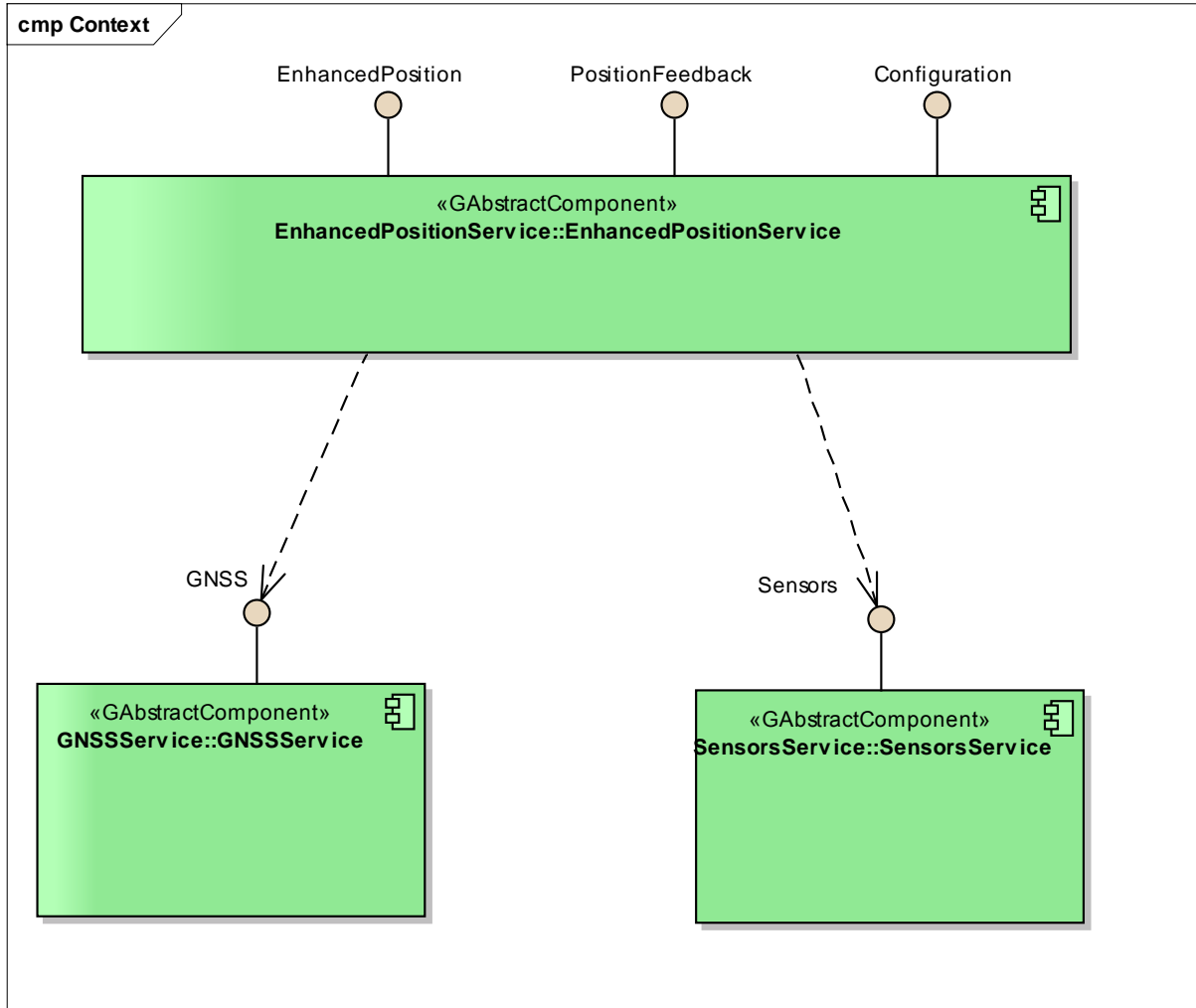


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1 **6.1.1 Component Dependencies**

2 The EnhancedPositionService depends on the following GENIVI components:

- 3 • GNSSService (library)
- 4 • SensorsService (library)

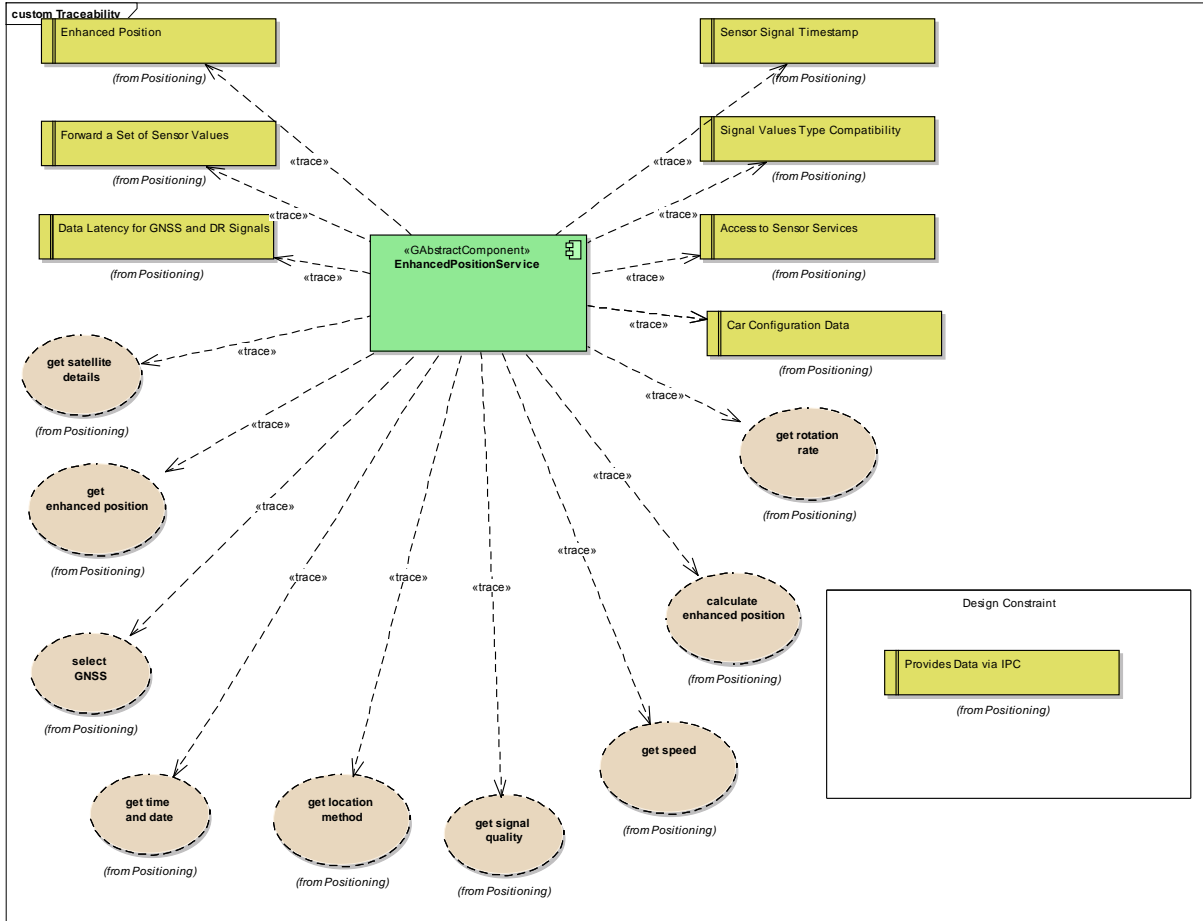


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### 2 6.1.2 Component Traceability

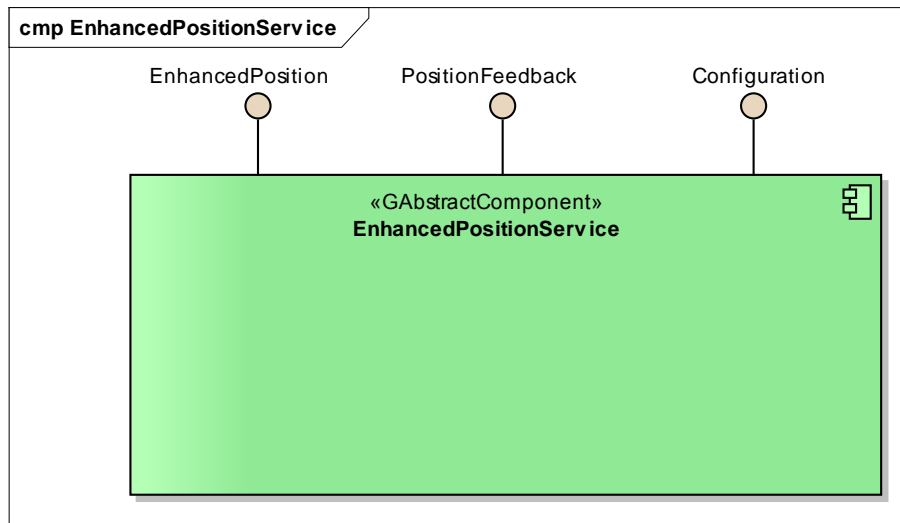
3 The following diagrams shows to which requirements and use cases realizations the EnhancedPositionService is  
4 traced to:



5

6

1

2 **6.2 EnhancedPositionService**

3

4 **6.2.1 Responsibility and Features**

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

6

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

11

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

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

15 **6.2.2 Provided Interfaces**

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

18

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

24

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

27 **6.2.3 Required Interfaces**

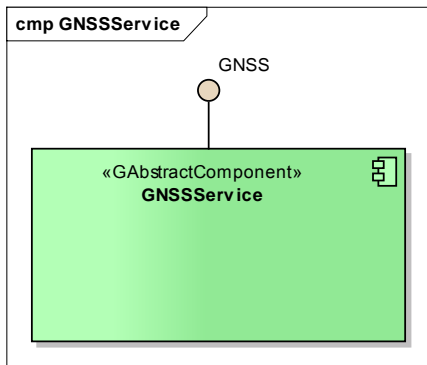
28 • **GNSS:** This interface abstracts the access to a GNSS device. Please see [\[1\]](#).

29 • **Sensors:** This interface abstracts the access to vehicle sensors. Please see [\[2\]](#).

30

1

## 2 6.3 GNSSService



3

### 4 6.3.1 Responsibility and Features

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

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

### 8 6.3.2 Provided Interfaces

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

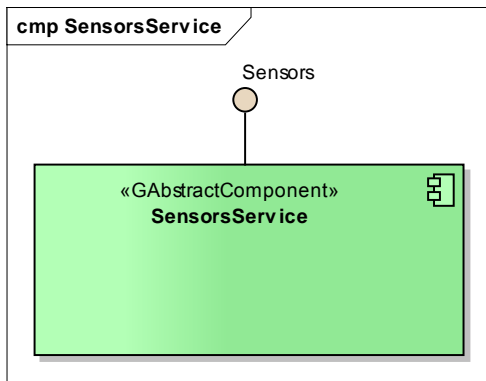
### 10 6.3.3 Required Interfaces

11 None.

12

1

## 2 6.4 SensorsService



3

### 4 6.4.1 Responsibility and Features

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

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

### 8 6.4.2 Provided Interfaces

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

### 10 6.4.3 Required Interfaces

11 None.

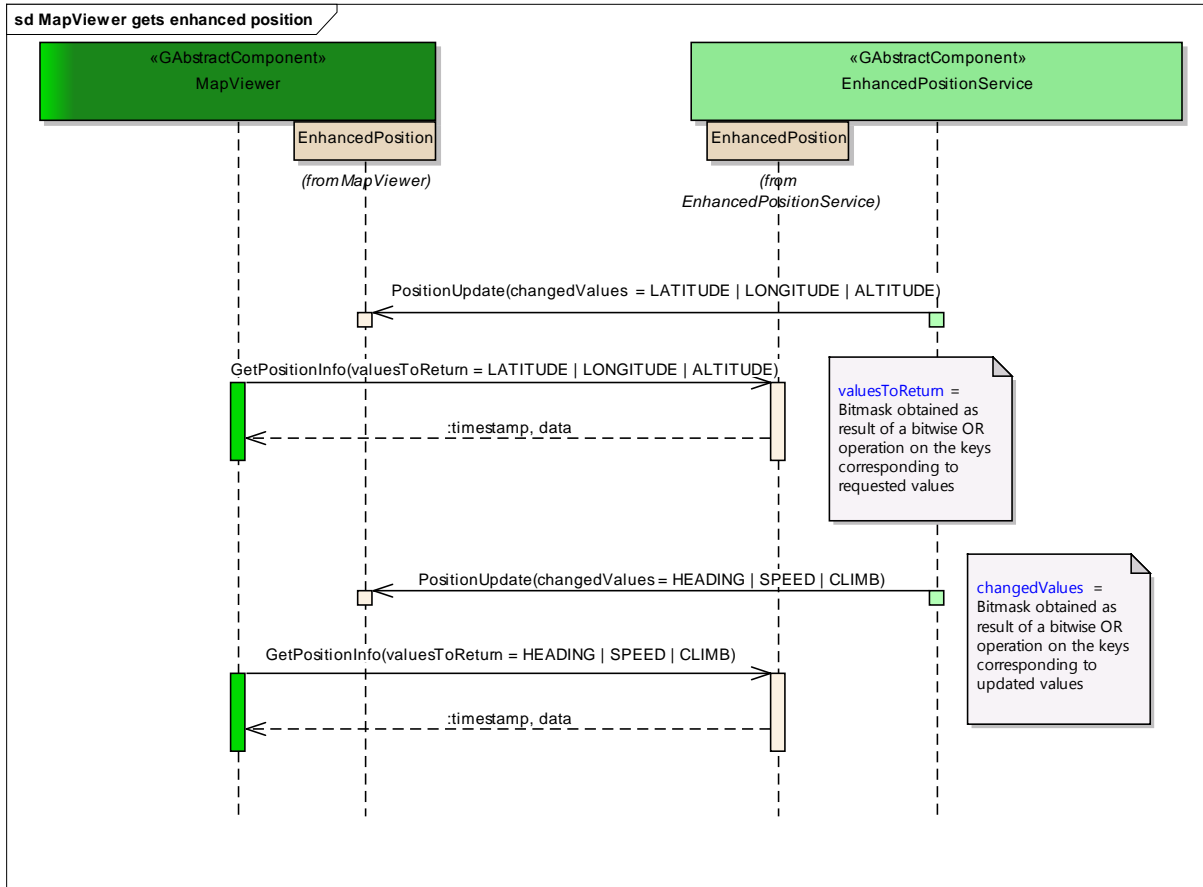
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# 7 Collaboration

## 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.



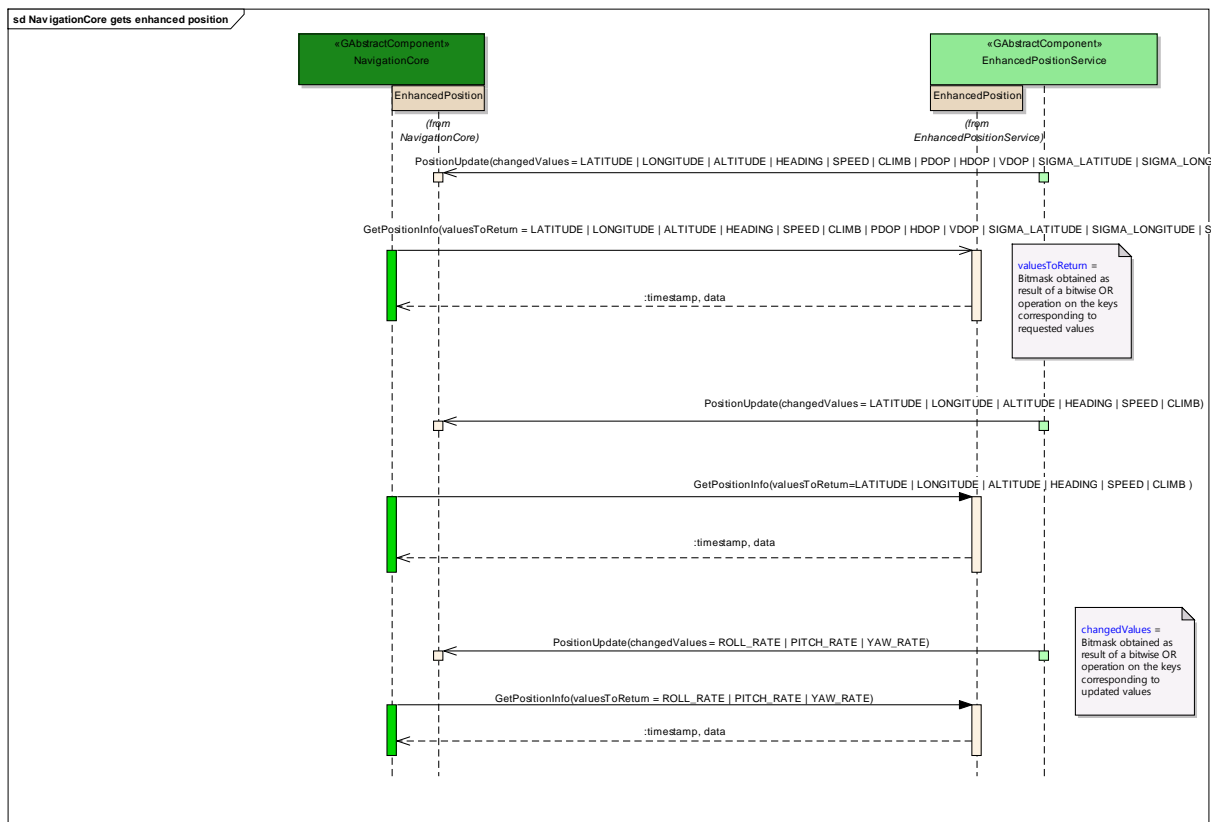
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1 **7.1.2 NavigationCore retrieves enhanced position**

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

3



4

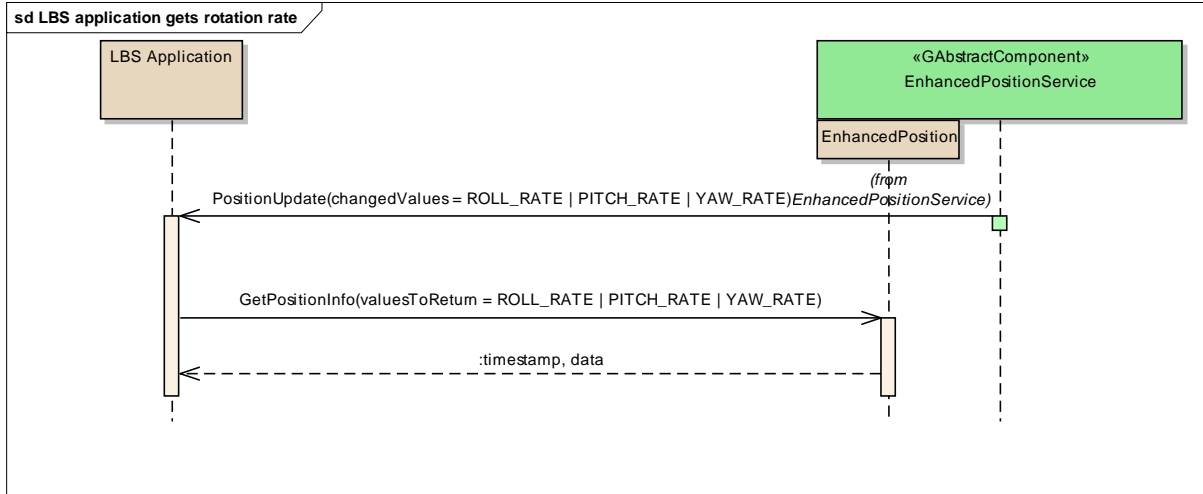
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1 **7.2 Get Rotation Rate**

2 **7.2.1 LBS Application retrieves rotation rate**

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

4



5

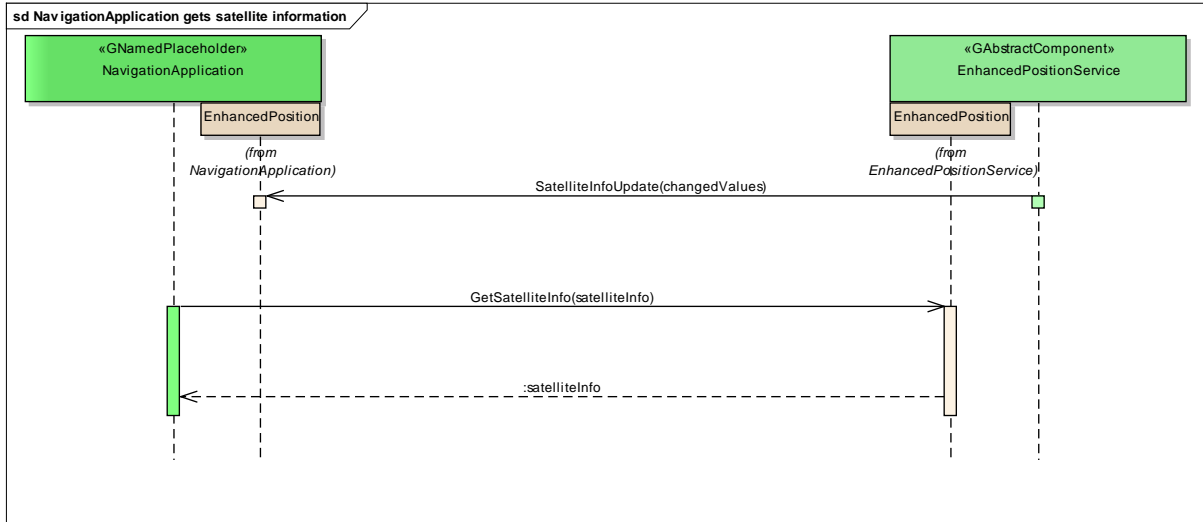
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1 **7.3 Get Satellite Details**

2 **7.3.1 Navigation Application retrieves satellite information**

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

4



5

6

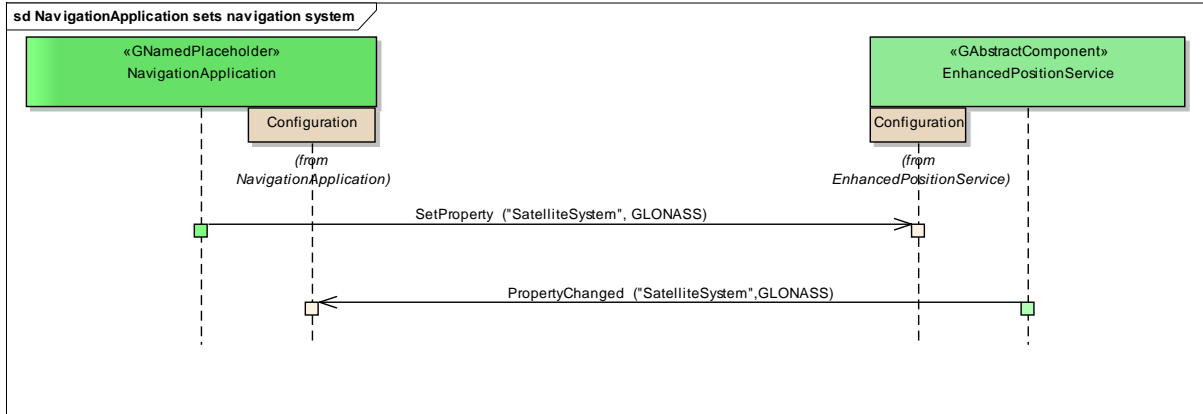
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2 **7.4 Set Navigation System**

3 **7.4.1 Navigation Application sets navigation system**

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

5



6

## 1 **8 Implementation**

2

### 3 **8.1 Available Implementation details**

4 A Proof of concept (PoC) of the EnhancedPositionService is available at:

5 <http://git.projects.genivi.org/?p=lbs/positioning.git;a=tree>

### 6 **8.2 Usage examples**

7 Please see: <http://git.projects.genivi.org/?p=lbs/positioning.git;a=tree;f=enhanced-position-service/test>.

### 8 **8.3 Test Plan**

9 Please see: [http://git.projects.genivi.org/?p=lbs/positioning.git;a=blob;f=enhanced-position-](http://git.projects.genivi.org/?p=lbs/positioning.git;a=blob;f=enhanced-position-service/doc/testplan.txt)  
10 [service/doc/testplan.txt](http://git.projects.genivi.org/?p=lbs/positioning.git;a=blob;f=enhanced-position-service/doc/testplan.txt)

## 9 Interfaces

The following pages describe the interfaces of the EnhancedPositionService.

### 9.1 D-Bus

The EnhancedPositionService interfaces are D-Bus interfaces. They are defined using the D-Bus introspection data format, which is nothing but an IDL expressed in XML format.

For more information about the D-Bus data types please refer to the following website:

<http://dbus.freedesktop.org/doc/dbus-specification.html#message-protocol-signatures>

For more information about the D-Bus introspection data format, please refer to the following website:

<http://dbus.freedesktop.org/doc/dbus-specification.html#introspection-format>

### 9.2 Git Repository

The EnhancedPositionService interfaces can be found in the GENIVI Git repository at:

<http://git.projects.genivi.org/?p=lbs/positioning.git;a=tree:f=enhanced-position-service/api>

### 9.3 Naming Conventions

Please see <http://dbus.freedesktop.org/doc/dbus-specification.html>.

<i>Element</i>	<i>Description</i>	<i>Example</i>
<i>Interface File</i>	<i>genivi.&lt;component name or domain in lowercase character&gt;.&lt;interface name in lowercase characters&gt;</i>	<i>org.genivi.positioning.Configuration</i>
<i>Methods/Signal/Properties</i>	<i>Camel case naming convention First letter uppercase</i>	<i>GetPositionInfo</i>
<i>Arguments</i>	<i>Camel case naming convention First letter lowercase</i>	<i>valuesToReturn</i>

### 9.4 Data Types Convention

D-bus types code are used. Please refer to the following webpage for more information:

<http://dbus.freedesktop.org/doc/dbus-specification.html>

<i>Element</i>	<i>D-Bus Data Type Code</i>	<i>Example</i>
<i>Enumerators</i>	<i>q (uint16)</i>	
<i>Handles</i>	<i>y (uint8)</i>	
<i>Maps</i>	<i>a{qv}</i>	<i>Dictionary of tuples (key, value) The key is expressed as an enumerator</i>

1

2 **9.5 Errors**

3

Error Type	Description	Example	Error Documentation	Note
User Error	Error caused by user actions	The user tries to start route guidance, although guidance is already running	Application specific error string documented in the XML file	Can occur in final product
Hardware Error	Error related to hardware/database related problems	No map data	Application specific error string documented in the XML file	Can occur in final product
Protocol Error	Error caused by wrong sequence of commands	Wrong sequence of commands to enter destination	Standard D-Bus error string	Should not occur in final product
Bus Error	D-Bus communication error	Bus busy	Standard D-Bus error string	Can occur in final product
Programming Error	Programming Error	Invalid parameters	Standard D-Bus error string and debug messages	Should not occur in production code

4

5 Only application-specific errors are documented directly in the interfaces (XML files). For all other errors,  
6 standard D-Bus strings are used. These kinds of strings are not documented in the interfaces. It is implicitly  
7 assumed that every method may return a standard D-Bus error string.

8

9 Please see [http://dbus.freedesktop.org/doc/api/html/group\\_\\_DBusProtocol.html](http://dbus.freedesktop.org/doc/api/html/group__DBusProtocol.html).

10