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Comparisons of Multipath Modeling Strategies for the Estimation of GPS Positioning Error

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I. INTRODUCTION

For precise GPS positioning one major source of error is multipath. Therefore, it is important to get information about the possible multipath signals in a complex scenario such as urban or suburban man-made environments. We can distinguish three kinds of prediction models in the literature. Deterministic models, based on an electromagnetic description of multipath, require a precise description of the 3D receiver’s environment in order to predict channel parameters [1]-[4]. Statistical models derive channel statistics by means of a statistical description of the environment based on extensive experimental data [5]-[6]. Finally, hybrid deterministic-statistic models are based on both deterministic techniques to simulate the basic characteristics of the channel and statistical add-ons [7]-[10]. The main interest of hybrid models is to achieve a realistic channel representation while maintaining an acceptable computation time in comparison to pure deterministic models. Here we focus on deterministic models. Most of them predict multipath by combining ray tracing techniques with geometrical optics (GO) or with the uniform theory of diffraction (UTD). Moreover, in these models the influence of small elements and material characteristics are generally not assessed in the simulation results.

In this article, we aim at two main objectives. The first objective is to propose a model based on physical optics (PO) in which field propagation is not approximated by rays, and to compare its performance with GO and UTD. The second objective is to specify a suitable description of the 3D environment (level of details and material characteristics) for multipath simulations.

In the next sections, we first introduce the GPS channel model, then we present GO, UTD and PO approaches. Finally simulations are performed to compare these approaches and to determine a suitable description of the environment.

II. PRESENTATION OF THE SIMULATION SOFTWARE

A. Channel Modeling

Between one satellite and the receiver, multipath corresponds to the fact that instead of receiving only the desired GPS signal, the antenna receives the aggregate of the direct signal and one or several reflected signals following indirect paths. If \( x(t) \) represents the emitted waveform by a satellite, the received signal \( y(t) \) is a sum of attenuated, time-delayed versions of \( x(t) \). Here we use the classical impulse response function \( h(t) \) for multipath channels given by [11]

\[
h(t) = \sum_{k=1}^{K} a_k \delta(t - \tau_k)e^{j\phi_k},
\]

with \( t \) the observation time, \( \delta \) the Dirac distribution and \( K \) the number of multipath components. Further, \( (a_k, \tau_k, \phi_k) \) are the amplitude (or gain), arrival time and phase of the \( k \)-th path, respectively. For the sake of this paper they are assumed time invariant. Finally, the channel is entirely described by the parameters \( (a_k, \tau_k, \phi_k) \) for \( k = 1...K \).

B. Principle of the Simulation

The principle of the complete simulator is illustrated in Fig. 1. The input parameters of the multipath generator are the satellite position, the receiver position, and the 3D modeling of the environment composed of planar dielectric and metallic facets. The role of the multipath generator is to predict the channel parameters. These parameters become the input of the GPS receiver simulator which returns the receiver position error.

![Fig. 1 Principle of the coupling between the multipath generator and the GPS receiver simulator](image-url)
The multipath generator is composed of two main blocks. The first one predicts the list of the electromagnetic fields associated with each multipath. These fields can be computed either by GO, UTD or PO. The second one simulates the GPS receiver antenna. It allows the computation of the multipath parameters \((a_k, \tau_k, \phi_k)\) from the electromagnetic fields via the use of the effective vectorial height of the antenna. In this paper we do not present the GPS receiver simulator developed by ENAC. Information about GPS receiver’s settings can be found in [12].

C. Geometrical Optics

For GO and UTD predictions we use MUSICA, a full-wave prediction software developed by ENAC [12]. With GO, each multipath corresponds to a single ray between the satellite, a facet and the receiver which respects Fermat Principle. The direct signal reaching the antenna and one reflection on a facade are illustrated in Fig. 2. With UTD, rays associated with edge diffraction are added.

![Fig. 2 Direct signal and one GO multipath due to a facade](image)

D. Physical Optics

1) Multipath Computation: We propose an approach to predict multipath using PO. Within this approach, each illuminated surface generates reflected field. Since the environment is described by a set of facets, each illuminated facet is at the origin of one multipath as illustrated in Fig. 3.

![Fig. 3 Direct signal and several PO multipath due to a facade](image)

Field amplitude and phase of each multipath are computed at the L1 frequency and delays correspond to the geometrical delays of the path satellite-facet-receiver. In order to reduce the computation time of the surface integral that appears for each facet with PO, we use the Mittra and Lee method described in [13]. This technique is only valid for receivers located in the far-field of each facet. Therefore, the facet size \(D\) must be chosen small enough so that the distance \(d\) between the receiver and the facets respects the condition

\[
d > 2D^2/\lambda \tag{1}\]

with \(\lambda\) the signal wavelength. Moreover, our PO approach takes into account double reflections between the facets and the ground assuming an infinite planar dielectric or metallic terrain.

2) Multipath Reduction: Since each illuminated facet generates a multipath, the computation load can become important in case of a complex 3D scene. In order to reduce the number of multipath we group adjacent multipath. If \((a_1, \tau_1, \phi_1)\) and \((a_2, \tau_2, \phi_2)\) are the characteristics of two multipath to be grouped, they are reduced as one equivalent multipath defined by

\[
a = |a_1 e^{j\phi_1} + a_2 e^{j\phi_2}|, \tag{2}
\]

\[
\tau = \frac{a_1^2 \tau_1 + a_2^2 \tau_2}{a_1^2 + a_2^2}, \tag{3}
\]

\[
\phi = \text{arg}(a_1 e^{j\phi_1} + a_2 e^{j\phi_2}). \tag{4}
\]

In order to ensure the validity of this multipath reduction, a criterion on the delays, \(\tau_1\) and \(\tau_2\) has to be defined. In the frequency domain, the sum of the two initial multipath corresponds to

\[
H(f) = a_1 e^{-j2\pi f \tau_1} e^{j\phi_1} + a_2 e^{-j2\pi f \tau_2} e^{j\phi_2}. \tag{5}
\]

Note that at the central frequency, i.e. \(f = 0\), we find back the equivalent values for \(a\) and \(\phi\). Introducing \(\tau\) in (5), we deduce that \(H\) may be reduced to one multipath if the condition

\[
a e^{j\phi} = a_1 e^{j\phi_1} e^{-j2\pi f (\tau_1 - \tau)} + a_2 e^{j\phi_2} e^{-j2\pi f (\tau_2 - \tau)}\tag{6}
\]

is respected in the entire GPS band. This leads to

\[
|B(\tau_1 - \tau_2)| \ll 1, \tag{7}
\]

where \(B\) is the bandwidth of the GPS L1 signal. Hence two multipath can be grouped only if their delays respect this condition. Moreover, all the multipath with a delay such that

\[
\tau > \frac{3}{2} T_C \tag{8}
\]

are rejected since they do not have any influence on the GPS position [12]. The code period \(T_C\) is given by \(1/F_C\) where \(F_C\) is the GPS L1 C/A code frequency (\(F_C = 1.023\)Mhz). Multipath delay of \(3T_C/2\) corresponds to a delay distance of approximately 440m. In our application we consider this distance as the observation range limit, which means that objects further than 440m from the receiver antenna are neglected.
III. SIMULATIONS

A. Methods Comparison

1) Configuration: In this section, we focus on the multipath generator of our prediction model (Fig. 1). We compare the ability of GO, UTD and PO to produce accurate channel parameters in canonical configurations in order to determine the best modeling choice.

We consider two scenes. The first one is a large rectangular metallic reflector of size (69.6m x 16.2m), which corresponds to an ENAC campus building (Fig. 4). The second scene is a smaller metallic rectangular reflector of size (3.3m x 1.6m), which may correspond to a window of the preceding building. Reflectors are faceted in squares of side 0.5m. The antenna is modeled as isotropic, right-hand circularly polarized (RHCP) and with a polarization mismatch factor of –5dB. The incident field coming from the satellite is a RHCP plane wave, with an incidence of azimuth $\theta = 45^\circ$ and elevation $\phi = 0^\circ$. Using (2), (3) and (4), multipath of delays less than $10^{-3} T_c$ are grouped.

2) Large reflector: In Fig. 5, we expose the Power Delay Profiles (PDP) $|h(t)|$ obtained with the different methods for a receiver located in front of the large metallic reflector.

![Fig. 4 Configuration of the simulations (the red dot represents the receiver position)](image1)

Fig. 4 Configuration of the simulations (the red dot represents the receiver position)

![Fig. 5 Comparison of the GO, UTD and PO Power Delay Profiles](image2)

Fig. 5 Comparison of the GO, UTD and PO Power Delay Profiles

The UTD PDP highlights the presence of one direct path, followed by one reflected 4 diffracted multipath. On the other hand, the PO reduced PDP (obtained after the multipath reduction process) shows one direct path followed by an important number of reflected multipath. Hence, it appears difficult to compare the PDPs of the channel models. To establish a comparison criterion, a more suitable way consists in looking at the results in the frequency domain. In Fig. 6, we observe the transfer functions obtained with PO, GO and UTD in the GPS frequency band. We denote that PO and UTD match, whereas slight differences exist if only GO is employed.

![Fig. 6 Transfer functions of the GPS multipath channel using the different modeling approaches](image3)

Fig. 6 Transfer functions of the GPS multipath channel using the different modeling approaches

Note also in this figure that the PO multipath reduction does not affect the PO channel transfer function. We define an average quadratic difference between 2 results $h_1(t)$ and $h_2(t)$ as

$$\epsilon_{mq} = \frac{\int_{-B/2}^{B/2} |S_{GPSL1}(f)|^2 df}{\int_{-B/2}^{B/2} |S_{GPSL1}|^2 df},$$

with $S_{GPSL1}$ the spectrum envelop of the GPS L1 signal. From the receiver point of view, two models predicting the same transfer functions in the GPS band are strictly equivalent. We can consider that two predictions fit correctly if $\epsilon_{mq} \leq -20dB$.

![Fig. 7 Average quadratic difference between: (a) PO and UTD, (b) PO and GO](image4)

Fig. 7 Average quadratic difference between: (a) PO and UTD, (b) PO and GO

In Fig. 7 (a) we depict $\epsilon_{mq}$ in the vicinity of the reflector at a height of 8.1m. We notice that PO and UTD match except at distances below one meter from the reflector where $\epsilon_{mq}$ is about 0dB. These significant differences are due to the fact...
that at this distance, we are not in the far-field of the facets as
imposed by (1), thus PO is not valid. To reduce this error in
PO, smaller facets can be employed, which will however yield
longer computation times. Fig. 7 (b) shows large differences
between GO and PO near the reflector, and also near the
shadow boundaries where $\epsilon_{mq}$ can be of order -5dB. Hence,
GO produces significant errors near the shadow boundaries.

3) Small reflector: We now focus on the case where the
reflector is smaller. Fig. 8 illustrates the field on the axis of
specular reflection.

In the far-field zone of the reflector, we observe significant
differences in the methods. Indeed, only PO gives consistent
results, i.e. a field that decreases in $1/r$ with $r$ the distance
from the reflector. UTD and GO results are non-physical
because there are caustics in the pencil of reflected and
diffracted rays [14]. Indeed, we consider an incident plane
wave on a planar object, and we observe in the far-field zone
of the reflector. Hence the UTD prediction only gives valid
results in the near-field zone of the reflector i.e. approximately
for

$$r < D^2/2\lambda. \quad (10)$$

4) Selection of the model: In the GPS context, for large
facades, the observation range of interest ($r \leq 440m$) remains
in the near-field zone of the object. In this configuration we
have shown that UTD and PO gives similar results while
differences exist with GO near the shadow boundaries. For
small planar objects, the observation range of interest may
reach the far-field zone of the object, inside which we have
observed non-physical results with UTD and GO.

At the maximum observation distance ($r = 440m$), the
minimal acceptable size of objects that GO and UTD can treat
may be estimated using (10), which leads to a limit of about
13m.

In this paper, we want to consider complex scenes with
objects of size few meters; therefore we choose to employ PO
in the next section.

B. Choice of an Appropriate Description of the Environment

1) Configuration and comparison criterion: We now employ
the complete prediction model of Fig. 1 in order to evaluate
the influence of the environment description. Notice that the
receiver range error is the determinant output when the
complete simulator is analyzed.

As a realistic configuration, we consider a complete 3D
model of the ENAC building (Fig. 9), described by means of
dielectric multilayer facets. The building is made of concrete
walls with glass windows. The ground is assumed to be
asphalt. The satellite azimuth and elevation angles are 45° and
15°, respectively. In the receiver, the RF front-end filter
bandwidth is set to 24Mhz, and the Early-minus-Late chip
spacing [12] has a value of 0.25Tc.

The total electric field at a height of 8.1m is depicted in Fig.
10.

In the following simulations, we analyze the range error for
a receiver located on a trajectory parallel to the x axis, at 20m
from the building, and at a height of 8.1m (Fig. 9). This error
is computed at each point for a static receiver and satellite.

2) Influence of few-meters element: First of all we want to
assess the influence of details in the scene. Hence we perform
simulations either with or without the windows in the 3D
modeling. Fig. 11 illustrates the range error between the
satellite and the receiver computed along the trajectory.

As could be expected there exists significant range error in
the specular reflection zone ($-20m \leq x \leq 50m$). Outside this
zone the residual error originates in the ground reflection.

The general behavior of the range error remains similar
regardless the presence of windows. However, windows
induce locally large oscillations of order of 10m.
3) Influence of materials characteristics: Next, we propose to assess the influence of the material characteristics. For this purpose we present simulations with different modeling parameters of the environment. Fig. 12 illustrates the receiver range error for hardened, reinforced and aerated concrete of permittivity $\varepsilon_r = 6.5 - j0.4$, $\varepsilon_r = 7 - j0.3$ and $\varepsilon_r = 2 - j0.5$, respectively [15].

![Fig. 12: GPS receiver estimated range error with concrete modeled as (a) hardened, (b) reinforced and (c) aerated](image)

Hardened and reinforced concrete modeling present similar impact on the range error. However, these differences become significant when concrete is modeled as aerated. This result shows the importance of a precise knowledge of the building materials for the estimation of multipath error.

IV. CONCLUSIONS

In this article, two objectives were planned: the choice of an appropriate electromagnetic multipath model, and a suitable description of the environment.

To this end, we have developed a 3D prediction software based on PO to model the impact of multipath onto GPS positioning error. It accounts for the 3D environment, the presence of a flat dielectric terrain, the receiver antenna and the GPS receiver behavior.

Simulations performed with this tool have shown that PO and UTD prediction match whenever the observation range remains in the near field zone of the element. In the far-field zone of the element only PO yields physical results. In GPS context, the minimal acceptable size of objects that GO or UTD can treat may be estimated at approximately 13m. Besides, GO is inaccurate near the shadow boundaries.

Concerning the environment description, we have observed that small elements, e.g. doors and windows, may have a significant influence on the receiver range error. However, they can be precisely accounted only if their dielectric characteristics are precisely known, which might not be the case with building materials for instance.

For future work, a complementary statistical prediction could be added to account for the lack of knowledge of the environment.

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