



## Track4 "Foot-Mounted IMU (offsite-online)" special features

### Organizational aspects:

#### Database/dataset access

- As initiated in Spain in 2021, Track4 is now an "offsite-online" track. That means, we ask competitors to process data **as if they were in real time**. To do so, an interface based on a web API has been developed: EvaalAPI. This API will be used by competitors for sending position estimates and reading the sensor values:  
<https://evaal.aaloo.org/evaalapi/>
- In the context of this EvaalAPI framework, two "scoring trials" ("scoring trial#1" and "scoring trial#2" described later) will be proposed to competitors. **Each of these scoring trials will be usable only once**. Competitors have thus two trials for the evaluation.
- In order to help competitors to be well prepared for the evaluation, a "testing trial" is proposed. This **"testing trial" is fully accessible and reloadable** (i.e. not restricted to a single usage as scoring trials). GroundTruth positions are included in the "testing trial" under the POSI<sup>1</sup> label, for validation purpose.
- Extract from <https://competition.ipin-conference.org/current-competition/call-for-competition> :  
*"OFFSITE-ONLINE TRACKS : Competitors are provided with sensors data and use them to estimate the user position. Competitors calibrate their algorithms in advance using ground truth reference data (testing trials) and compete using new unreferenced data (scoring trials). Competitors run their Trials through the EvaalAPI in the usual online mode to emulate the causal, real-time behaviour of onsite Tracks. Scoring trials are run on a Track-specific day during the second week of September."*

#### Competitor admission process / Application:

- Admission process: <https://competition.ipin-conference.org/current-competition/call-for-competition>
- Application page: <https://competition.ipin-conference.org/current-competition/application>

#### Submission of the processed results

- As mentioned earlier, results have to be submitted via a web API. See above.
- A participant team can run the process up to 2 times. This provides a chance to catch-up if any issues happen. Although the competition organizers will evaluate the two scoring trials, only the best one will be considered for the contest. These two datasets correspond to two different data collections performed on the same path but not at the same time.

#### Important deadlines:

- Technical annexes published **May, 2024**
- "testing trial" is accessible through web API **July, 2024**
- Application deadline **September 7<sup>th</sup>, 2024**
- "testing trial" fully executed with web API **September 15<sup>th</sup>, 2024**
- **"scoring trial#1" and "scoring trial#2" will be accessible** **Sept 25<sup>th</sup> - Oct. 4<sup>th</sup> 2024**
- Proclamation of winners **October 17<sup>th</sup>, 2024**

<sup>1</sup> See hereafter in the document, for details

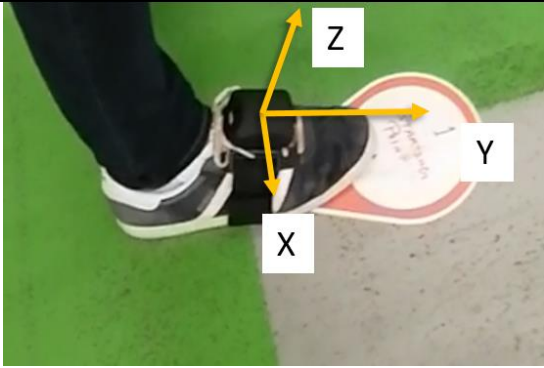
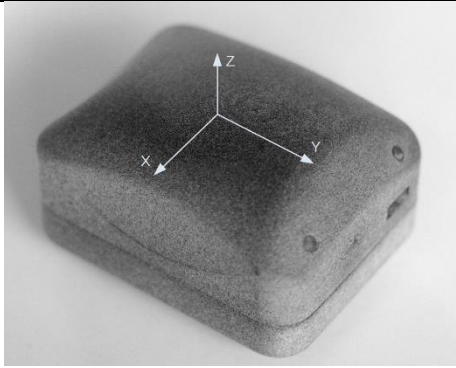


Scope

Many indoor navigation systems have been developed for pedestrians and assessing their performances is a real challenge. Benefiting from a reference solution that is accurate enough to evaluate other indoor navigation systems and assist novel research is of prime interest. According to ISO18305:2016 two different ways can be used for assessing indoor localization system: “Off-line surveyed test point” that is commonly used, or “reference system” with an accuracy at least one order of magnitude better the system you want to test. The scope of this track4 is clearly focused on the second way of assessing. This track4 is based on the same equipment named “ULISS” as it is for several years now.



Competition Goal

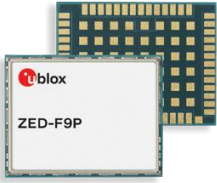
The goal of this competition is to evaluate how good up-to-date INS algorithm is. Each competitor will have access to a dataset logged with ULISS (Ubiquitous Localization with Inertial Sensors and Satellites), a state-of-the-art Inertial Navigation System producing IMU data, MAG data, PRESSURE data & GNSS data, without the help of any maps.

 <p>ULISS sensor installed on the right foot (with axes), on the starting point.</p>	 <p>ULISS sensors axes</p>
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Description of Datasets

Data is recorded from 3 different sensors:

<p>Xsens Mti-7</p> 	<p>IMU-Mag sensor:                  -3D accelerometer                  -3D gyrometer                  -3D magnetometer</p> <p><a href="https://www.xsens.com/mti-7">https://www.xsens.com/mti-7</a></p>
<p>BMP280 sensor</p> 	<p>Operation range: Pressure: 300...1100 hPa                  Absolute accuracy : ~ ±1 hPa                  Relative accuracy : ± 0.12 hPa (typical)</p> <p><a href="https://www.bosch-sensortec.com/products/environmental-sensors/pressure-sensors/bmp280/">https://www.bosch-sensortec.com/products/environmental-sensors/pressure-sensors/bmp280/</a></p>
<p>Ublox ZED-F9P dual freq. receiver</p>	<p>Multi GNSS Receiver : BeiDou, Galileo, GLONASS, GPS / QZSS                  Number of concurrent GNSS 4                  Dual GNSS Bands : L1C/A, L2C, L1OF, L2OF, E1B/C, E5b, B1I, B2I</p>



<https://www.u-blox.com/en/product/zed-f9p-module>

Unit and meaning of the sensors outputs of ULISS are the following ones:

Column	Xsens MTi-1 (accelerometer)	Comments
1	Acceleration label	"ACCE"
2	GPS Time of Week (ToW) in second	GPS Time of Week (ToW) in second
3	Acc X (m/s <sup>2</sup> )	
4	Acc Y (m/s <sup>2</sup> )	
5	Acc Z (m/s <sup>2</sup> )	

Sample strings for accelerometer data

```
ACCE,314410.003952000,-1.25709,-4.34142,8.75831
ACCE,314410.008947000,-1.23771,-4.28408,8.72497
ACCE,314410.013942000,-1.26714,-4.3795,8.72491
ACCE,314410.018937000,-1.26167,-4.29823,8.71566
ACCE,314410.023932000,-1.25662,-4.26479,8.71095
```

Column	Xsens MTi-1 (gyrometer)	Comments
1	Gyrometer label	"ROTA"
2	GPS Time of Week (ToW) in second	GPS Time of Week (ToW) in second
3	Gyro X (rad/s)	
4	Gyro Y (rad/s)	
5	Gyro Z (rad/s)	

Sample strings for gyrometer data

```
ROTA,314410.004573000,0.00275338,-0.000805736,0.006387
ROTA,314410.009578000,-0.00576329,-0.00401807,0.00535798
ROTA,314410.014582000,0.00813067,0.00989926,0.00747764
ROTA,314410.019587000,0.00594413,-0.00079453,0.00529695
ROTA,314410.024591000,0.00488472,0.00237882,0.0117271
```

Column	Xsens MTi-1 (magnetometer)	Comments
1	Magnetometer label	"MAGN"
2	GPS Time of Week (ToW) in second	GPS Time of Week (ToW) in second
3	Mag X (a.u.)	a.u. = arbitrary unit according to Xsens.
4	Mag Y (a.u.)	Tips : multiply by 0.49*1000,
5	Mag Z (a.u.)	In order to get milliGauss (mG)

Sample strings for magnetometer data

```
MAGN,314410.005162000,0.224368,0.435266,-1.14962
MAGN,314410.015162000,0.22387,0.434764,-1.14766
MAGN,314410.025162000,0.222876,0.438141,-1.1481
MAGN,314410.035162000,0.223393,0.433828,-1.14817
MAGN,314410.045162000,0.224333,0.431291,-1.1413
```



Column	BMP280 (pressure)	Comments
1	Pressure sensor label	"PRES"
2	GPS Time of Week (ToW) in second	GPS Time of Week (ToW) in second
3	Pressure (Pa)	

Sample strings for pressure data

```
PRES,314410.005162000,101144
PRES,314410.025162000,101152
PRES,314410.045162000,101138
PRES,314410.065162000,101151
PRES,314410.085162000,101151
```

Column	Temperature (temperarure)	Comments
1	Temperature sensor label	"TEMP"
2	GPS Time of Week (ToW) in second	GPS Time of Week (ToW) in second
3	Temperature (Degree Celsius)	

Sample strings for temperature data

```
TEMP,314410.025162000,44.1914
TEMP,314411.025162000,44.1758
TEMP,314412.025162000,44.1758
```

Column	Ublox F9P GNSS receiver (SBS)	Comments
1	GNSS SBAS information label	"GSBS"
2	GPS Time of Week (ToW) in second	GPS Time of Week (ToW) in second
3	Hexadecimal WORD	Corresponds to EGNOS SBAS Message Format*

\*: [https://gssc.esa.int/navipedia/index.php/The EGNOS SBAS Message Format Explained](https://gssc.esa.int/navipedia/index.php/The_EGNOS_SBAS_Message_Format_Explained)

Sample strings for SBS (SBAS – EGNOS) data

```
GSBS,315499,9A494C0000000000000400001F00003F80003FC0003FE0001FF0001FF80
GSBS,315618,5363FBFFDC000000000000197BBBAA01848160A0580B185BFDFF980900
GSBS,315619,9A0A8003FE4027FFBFC7FEFFD4003FEC000003FB8003959559797BA380
```

Column	Ublox F9P GNSS receiver (SBS)	Comments
1	GNSS Observation label	"GOBS"
2	GPS Time of Week (ToW) in second	GPS Time of Week (ToW) in second
3	Observation data	Observation file based on RINEX 3.04 format <a href="http://rtcm.info/RINEX_3.04.IGS.RTCM_Final.pdf">http://rtcm.info/RINEX 3.04.IGS.RTCM_Final.pdf</a> Only data after header* is used in the context of Track4.

\*Header of "OBSERVATION DATA" file under Rinex 3.04 format are given later in each session specific parts (headers are slightly different).

Sample strings for OBS (observation file, based on RINEX 3.04 format) data

```
GOBS,314856.199000000,G04 24066762.037 8 126471694.10925 -3666.900 39.000
GOBS,314856.199000000,G09 21204418.682 8 9 -2579.258 24.000
GOBS,314856.199000000,G06 21843663.561 9 9 -3361.335 14.000
GOBS,314856.199000000,C24 24066200.488 4 9 -1496.777 42.000
GOBS,314856.199000000,C09 41038802.886 9 213699815.76337 -1391.943 30.000
```



GOBS, 314856.199000000, R10	20885796.375	8	111333055.23728	-1125.414	35.000	
GOBS, 314856.199000000, R17	21027399.505	9	112521861.85837	1.771	31.000	
GOBS, 314856.199000000, G16	24420695.497	9		-607.284	34.000	
GOBS, 314856.199000000, E25	26416183.541	9		1623.139	22.000	
GOBS, 314856.199000000, R09	23641111.957	9		-3901.952	26.000	
GOBS, 314856.199000000, E24	27240945.515	8		-857.287	38.000	
GOBS, 314856.199000000, E05	27154158.133	8		-2871.781	35.000	
GOBS, 314856.399000000, G04	24066902.088	8	126472426.50726	-3656.825	35.000	
GOBS, 314856.399000000, G09	21204516.880	8		-2576.887	25.000	
GOBS, 314856.399000000, G06	21843791.401	9		-3361.335	14.000	
GOBS, 314856.399000000, C24	24066258.112	4	125319321.10437	-1491.643	44.000	
GOBS, 314856.399000000, C09	41038856.136	8	213700093.52228	-1387.629	30.000	
GOBS, 314856.399000000, R10	20885839.907	8	111333279.85427	-1119.290	37.000	
...						
GOBS, 316465.400000000, G09	22053796.355	9		-2965.625	42.000	22053774.011 9
9	-2311.088	23.000				
GOBS, 316465.400000000, G06	22958748.483	8		-3890.580	43.000	22958742.892 9
9	-3018.360	18.000				
GOBS, 316465.400000000, G04	25190987.721	9		-3672.705	35.000	
GOBS, 316465.400000000, G20	20618874.632	4		1326.448	48.000	
GOBS, 316465.400000000, G07	20956968.745	8		-528.696	32.000	
GOBS, 316465.400000000, C14	26537412.626	9		-3269.531	39.000	

Column	ground truth position	Comments
1	ground truth position label	"POSI"
2	GPS Time of Week (ToW) in second	GPS Time of Week (ToW) in second
3	WGS84 longitude in decimal degrees	
4	WGS84 latitude in decimal	
5	Floor Number in integer	0 : Ground Floor, -X : for downstairs number X Y : for upstairs floor n° Y
6	POSI number index	

Sample strings for ground truth position data

POSI, 308945.294, -1.6313191524195993, 47.22617430160391, -1, 1
POSI, 308960.836, -1.6310604539849840, 47.22612380681056, -1, 2

Note1: POSI frame is only used twice in scoring trials. For the first Key Point (n°1) and the second Key Point (n°2).

Note2: POSI frame is used in testing trial to help competitors to tune their algorithm.



**Testing Trial:** dataset recorded around 12h00 (local time), the 29th of April 2024 in Nantes (France)

Type	Description	URL to download
<b>Testing Trial</b>	CSV file containing all data as described in section "Description of Datasets". GroundTruth is given inside IPIN2024_T4_TestingTrial_v1.txt	<a href="https://data.d4science.net/KGKr">https://data.d4science.net/KGKr</a>
<b>Ground Truth</b>	Ground Truth of TestingTrial given @60Hz for offline evaluation purpose.	matlab file: <a href="https://data.d4science.net/Zzea">https://data.d4science.net/Zzea</a> Python file: <a href="https://data.d4science.net/yyez">https://data.d4science.net/yyez</a> kml file: <a href="https://data.d4science.net/WLES">https://data.d4science.net/WLES</a>
<b>Tutorial</b>	Python script given as an example to play with Your specific TestingTrial name (TT) : run 2024_Track4_EvaalAPI_example.py "TT"	Python files: <a href="https://data.d4science.net/VGbA">https://data.d4science.net/VGbA</a>
<b>Allan Variance</b>	static logfile of about 14 hours that can be used for sensors bias estimation.	<a href="https://data.d4science.net/3Hyg">https://data.d4science.net/3Hyg</a>
<b>Magnetometer Calibration</b>	logfile of about 1 minute that can be used to calibrate the magnetometer sensor	<a href="https://data.d4science.net/HPRZ">https://data.d4science.net/HPRZ</a>
<b>GNSS Navigation file</b>	contains ephemeris data for those who want to use GNSS sensor.(format RINEX 3.04)	<a href="https://data.d4science.net/mT5X">https://data.d4science.net/mT5X</a>
<b>GNSS Observation header</b>	<pre> 3.04          OBSERVATION DATA      M: Mixed RTKCONV demo5 b34i                   20240528 092959 UTC format: u-blox UBX log: D:\IPIN2024\2024.04.29 J1 CiteCongres\ULISS\uliss-1-tra </pre>	<pre> RINEX VERSION / TYPE PGM / RUN BY / DATE COMMENT MARKER NAME MARKER NUMBER MARKER TYPE OBSERVER / AGENCY REC # / TYPE / VERS ANT # / TYPE APPROX POSITION XYZ ANTENNA: DELTA H/E/N SYS / # / OBS TYPES SYS / # / OBS TYPES SYS / # / OBS TYPES SYS / # / OBS TYPES SYS / # / OBS TYPES TIME OF FIRST OBS TIME OF LAST OBS SYS / PHASE SHIFT SYS / PHASE SHIFT SYS / PHASE SHIFT SYS / PHASE SHIFT SYS / PHASE SHIFT SYS / PHASE SHIFT SYS / PHASE SHIFT SYS / PHASE SHIFT GLONASS SLOT / FRQ # GLONASS SLOT / FRQ # GLONASS COD/PHS/BIS END OF HEADER </pre>
<b>RINEX 3.04 spec</b>	Specification of RINEX format version 3.04	<a href="https://data.d4science.net/a3Jn">https://data.d4science.net/a3Jn</a>



- **Note about Maps use**

- Usage of maps as an input for the computation of position estimates is **not allowed**. Track chairs, in such a case, could cancel contributions of competitor.
- Algorithms are not supposed to embed or access maps to enhance positioning. However, maps can still be used in the scope of auto-assessment during the preparation phase (Testing Trial).

- **Key Points:**

- All reference points are given at a sampling rate  $\sim 60\text{Hz}$ , for offline evaluation purpose.
- 32 ground truth key points will be given as POSI lines through EvalAPI.
- Among them the two first are important, because they can be used to compute a good heading like for “Scoring Trial” sessions (see Key Point n°1 and Key Point n°2 below).
- Evaluation is based like other Tracks: i.e. position estimates have to be computed and sent twice a second ( $\sim 2\text{Hz}$ ; i.e. EvalAPI horizon of 0.5s), synchronized with the eval data stream, and thus corresponding to the end of each dataset window of 0.5s.
- The output format is described in the chapter “Description of the Output File” here after.

- **Points given in order to get a good first heading:**

Two reference points are given to competitor in order to help them.

- **Coordinates of Key Point n°1 (starting point):**

- GPS Time of Week in seconds: 136589.274 s
- WGS84 longitude in decimal degrees:  $-1.544067019^\circ$
- WGS84 latitude in decimal degrees:  $47.213450998^\circ$
- Floor Number in integer: 0
- Corresponding POSI line:  
POSI,136589.274,-1.544067019,47.213450998,0,1

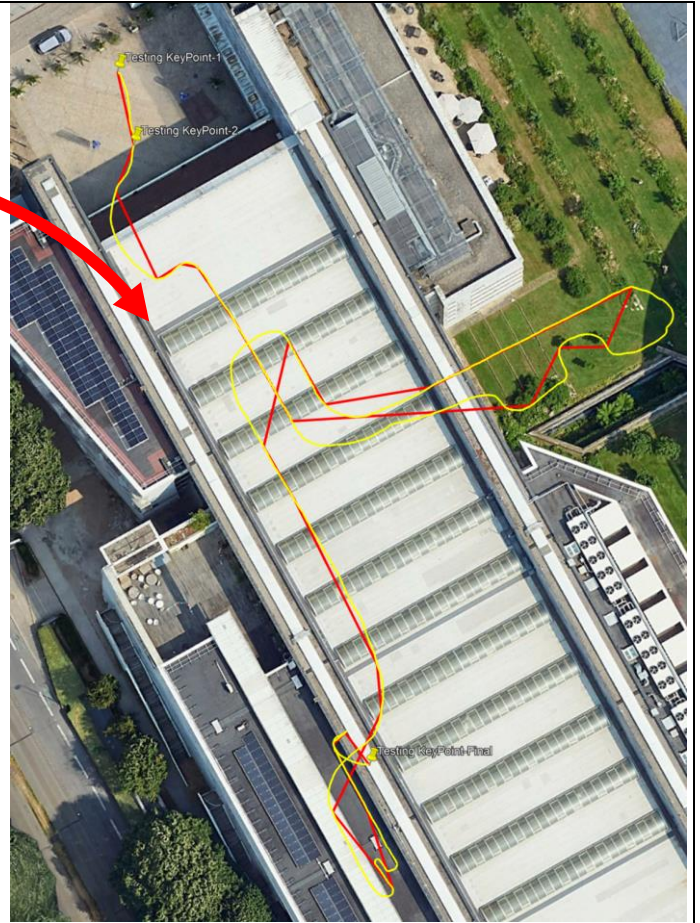
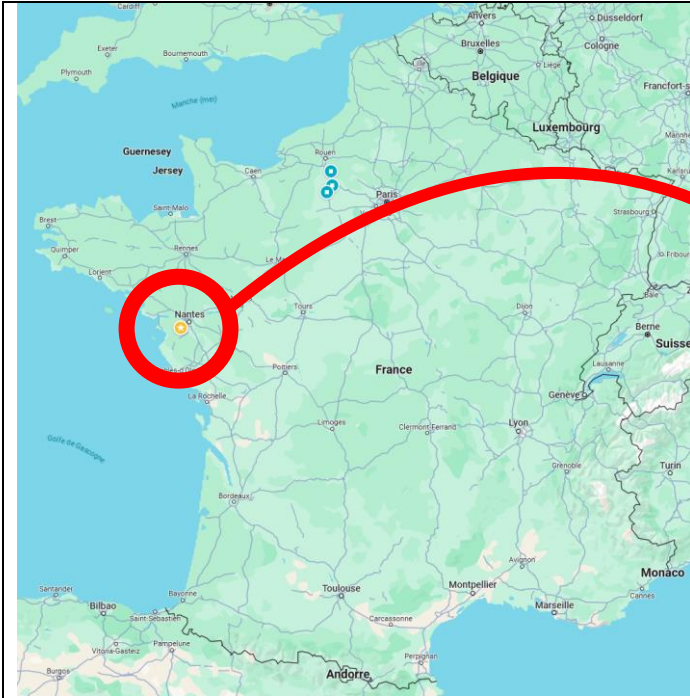
- **Coordinates of Key Point n°2 (at less than  $\sim 10\text{m}$  far from starting point):**

- GPS Time of Week in seconds: 136644.974 s
- WGS84 longitude in decimal degrees:  $-1.544040845^\circ$
- WGS84 latitude in decimal degrees:  $47.213371505^\circ$
- Floor Number in integer: 0
- Corresponding POSI line:  
POSI,136644.974,-1.544040845,47.213371505,0,2





• Bird view:



Legend:

- yellow = ground truth @60Hz for post-process evaluation (matlab & kml files)
- red = sub sample (32 key points) of ground truth given as POSI lines through EvaalAPI





**Scoring Trial#1: dataset recorded around 12h30 (local time), the 29th of April 2024 in Nantes (France)**

Type	Description	URL to download
<b>Scoring Trial</b>	<u>SCORING TRIAL is only accessible via EvaalAPI</u>	-
<b>Allan Variance</b>	static logfile of about 14 hours that can be used for sensors bias estimation.	<a href="https://data.d4science.net/3Hyg">https://data.d4science.net/3Hyg</a>
<b>Magnetometer Calibration</b>	logfile of about 1 minute that can be used to calibrate the magnetometer sensor	<a href="https://data.d4science.net/HPRZ">https://data.d4science.net/HPRZ</a>
<b>GNSS Navigation file</b>	contains ephemeris data for those who want to use GNSS sensor.(format RINEX 3.04)	<a href="https://data.d4science.net/2aMZ">https://data.d4science.net/2aMZ</a>
<b>GNSS Observation header</b>	<pre> 3.04          OBSERVATION DATA      M: Mixed          RINEX VERSION / TYPE RTKCONV demo5 b34i          20240918 153258 UTC PGM / RUN BY / DATE format: u-blox UBX          COMMENT log: D:\IPIN2024\2024.04.29 J1 CiteCongres\ULISS\uliss-1-traCOMMENT MARKER NAME MARKER NUMBER MARKER TYPE OBSERVER / AGENCY REC # / TYPE / VERS ANT # / TYPE APPROX POSITION XYZ ANTENNA: DELTA H/E/N SYS / # / OBS TYPES G 8 C1C L1C D1C S1C C2X L2X D2X S2X R 8 C1C L1C D1C S1C C2C L2C D2C S2C E 8 C1X L1X D1X S1X C7X L7X D7X S7X S 4 C1C L1C D1C S1C C 8 C2I L2I D2I S2I C7I L7I D7I S7I 2024 04 29 14 32 23.2040000 GPS 2024 04 29 15 19 22.4050000 GPS G L1C G L2X 0.00000 R L1C R L2C E L1X 0.00000 E L7X 0.00000 S L1C C L2I C L7I 11 R03 5 R04 6 R05 1 R06 -4 R10 -7 R11 0 R12 -1 R19 3 GLONASS SLOT / FRQ # R20 2 R21 4 R25 -5 C1C 0.000 C1P 0.000 C2C 0.000 C2P 0.000 GLONASS SLOT / FRQ # GLONASS COD/PHS/BIS END OF HEADER                     </pre>	
<b>RINEX 3.04 spec</b>	Specification of RINEX format version 3.04	<a href="https://data.d4science.net/a3Jn">https://data.d4science.net/a3Jn</a>



- **Note about Maps use**

- Even if maps may be allowed in others tracks, for this one, **it is NOT**. Track chairs, in such a case, could cancel contributions of competitor.
- Algorithms are not supposed to embed or access maps to enhance positioning.

- **Key Points:**

- Only 2 ground truth key points will be given as POSI lines through EvaalAPI (see Key Point n°1 and Key Point n°2 below).
- Evaluation is based like other Tracks: i.e. position estimates have to be computed and sent twice a second (~2Hz), synchronized with the eval data stream, and thus corresponding to the end of each dataset window of 0.5s.
- Based on previous point, Track4 is now able to assess all estimations computed by competitors. Thus, last edition, for instance, more than 3000 key points were evaluated for each run of competitors.
- The output format is described in the chapter “Description of the Output File” here after.

- **Points given in order to get a good first heading:**

Two reference points are given to competitor in order to help them.

- **Coordinates of Key Point n°1 (starting point):**

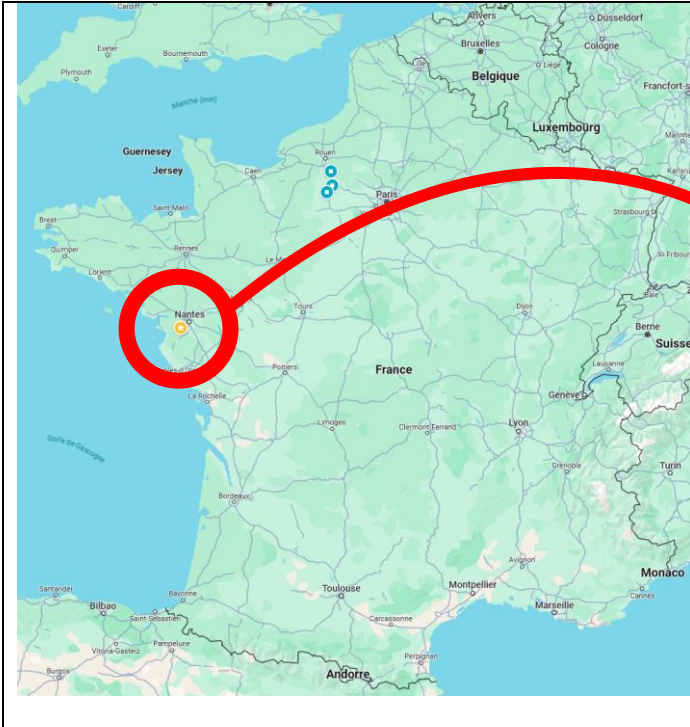
- GPS Time of Week in seconds: **138890.453**
- WGS84 longitude in decimal degrees: **-1.544066992**
- WGS84 latitude in decimal degrees: **47.213451666**
- Floor Number in integer: **0**
- Corresponding POSI line:  
**POSI,138890.453,-1.544066992,47.213451666,0,1**

- **Coordinates of Key Point n°2 (at less than ~10m far from starting point):**

- GPS Time of Week in seconds: **138906.186**
- WGS84 longitude in decimal degrees: **-1.544023383**
- WGS84 latitude in decimal degrees: **47.213380729**
- Floor Number in integer: **0**
- Corresponding POSI line:  
**POSI,138906.186,-1.544023383,47.213380729,0,2**



- **Bird view:**





**Scoring Trial#2: dataset recorded around 10h30 (local time), the 30th of April 2024 in Nantes (France)**

Type	Description	URL to download
<b>Scoring Trial</b>	<u>SCORING TRIAL is only accessible via EvaalAPI</u>	-
<b>Allan Variance</b>	static logfile of about 14 hours that can be used for sensors bias estimation.	<a href="https://data.d4science.net/3Hyg">https://data.d4science.net/3Hyg</a>
<b>Magnetometer Calibration</b>	logfile of about 1 minute that can be used to calibrate the magnetometer sensor	<a href="https://data.d4science.net/HPRZ">https://data.d4science.net/HPRZ</a>
<b>GNSS Navigation file</b>	contains ephemeris data for those who want to use GNSS sensor.(format RINEX 3.04)	<a href="https://data.d4science.net/4evg">https://data.d4science.net/4evg</a>
<b>GNSS Observation header</b>	<pre> 3.04      OBSERVATION DATA      M: Mixed      RINEX VERSION / TYPE RTKCONV demo5 b34i      20240918 153703 UTC PGM / RUN BY / DATE format: u-blox UBX      COMMENT log: D:\IPIN2024\2024.04.30 J2 CiteCongres\ULISS\uliss-1-traCOMMENT MARKER NAME MARKER NUMBER MARKER TYPE OBSERVER / AGENCY REC # / TYPE / VERS ANT # / TYPE APPROX POSITION XYZ ANTENNA: DELTA H/E/N G 8 C1C L1C D1C S1C C2X L2X D2X S2X SYS / # / OBS TYPES R 8 C1C L1C D1C S1C C2C L2C D2C S2C SYS / # / OBS TYPES E 8 C1X L1X D1X S1X C7X L7X D7X S7X SYS / # / OBS TYPES S 4 C1C L1C D1C S1C SYS / # / OBS TYPES C 8 C2I L2I D2I S2I C7I L7I D7I S7I SYS / # / OBS TYPES 2024 04 30 08 24 39.0050000 GPS TIME OF FIRST OBS 2024 04 30 09 11 42.0060000 GPS TIME OF LAST OBS G L1C SYS / PHASE SHIFT G L2X 0.00000 SYS / PHASE SHIFT R L1C SYS / PHASE SHIFT R L2C SYS / PHASE SHIFT E L1X 0.00000 SYS / PHASE SHIFT E L7X 0.00000 SYS / PHASE SHIFT S L1C SYS / PHASE SHIFT C L2I SYS / PHASE SHIFT C L7I SYS / PHASE SHIFT 11 R01 1 R06 -4 R07 5 R08 6 R09 -2 R10 -7 R15 0 R16 -1 GLONASS SLOT / FRQ # R17 4 R18 -3 R19 3 GLONASS SLOT / FRQ # C1C 0.000 C1P 0.000 C2C 0.000 C2P 0.000 GLONASS COD/PHS/BIS END OF HEADER </pre>	
<b>RINEX 3.04 spec</b>	Specification of RINEX format version 3.04	<a href="https://data.d4science.net/a3Jn">https://data.d4science.net/a3Jn</a>



- **Note about Maps use**

- Even if maps may be allowed in others tracks, for this one, **it is NOT**. Track chairs, in such a case, could cancel contributions of competitor.
- Algorithms are not supposed to embed or access maps to enhance positioning.

- **Key Points:**

- Only 2 ground truth key points will be given as POSI lines through EvaalAPI (see Key Point n°1 and Key Point n°2 below).
- Evaluation is based like other Tracks: i.e. position estimates have to be computed and sent twice a second (~2Hz), synchronized with the eval data stream, and thus corresponding to the end of each dataset window of 0.5s.
- Based on previous point, Track4 is now able to assess all estimations computed by competitors. Thus, last edition, for instance, more than 3000 key points were evaluated for each run of competitors.
- The output format is described in the chapter “Description of the Output File” here after.

- **Points given in order to get a good first heading:**

Two reference points are given to competitor in order to help them.

- **Coordinates of Key Point n°1 (starting point):**

- GPS Time of Week in seconds: **203222.473**
- WGS84 longitude in decimal degrees: **-1.544067347**
- WGS84 latitude in decimal degrees: **47.213450986**
- Floor Number in integer: **0**
- Corresponding POSI line:  
**POSI,203222.473,-1.544067347,47.213450986,0,1**

- **Coordinates of Key Point n°2 (at less than ~10m far from starting point):**

- GPS Time of Week in seconds: **203232.723**
- WGS84 longitude in decimal degrees: **-1.544033899**
- WGS84 latitude in decimal degrees: **47.213394268**
- Floor Number in integer: **0**
- Corresponding POSI line:  
**POSI,203232.723,-1.544033899,47.213394268,0,2**





- **Bird view:**





### Description of the Output stream to return by competitor

For each scoring trial, competitor is asked to give processed data inside the field “position estimates” of the *GET/TRIAL/nextdata* EvaalAPI request. The string “position” has to be composed of the 4 following fields:

- Field 1: WGS84 longitude in decimal degrees with at least 9 decimal digit resolution
- Field 2: WGS84 latitude in decimal degrees with at least 9 decimal digit resolution
- Field 3: Floor Number in integer. 0 for Ground Floor, -X for downstairs number X, Y for upstairs floor n° Y
- Field 4: Incrementing counter starting from 1. 1 being the first point computed by competitor, 2 being the second, and so on...

Comma (“,”) has to be used as data delimiter.

Assessment will take into account the PTS (timestamp relative to the last position) return by *GET/TRIAL/estimates* EvaalAPI request.

Examples of successive string “position estimates” included in *GET/TRIAL/nextdata* requests:

```
-1.542614572,47.217689856,0,1  
-1.542614573,47.217689855,0,2  
-1.542614574,47.217689854,2,3  
...
```

Corresponding example of *GET/TRIAL/estimates* request:

```
pts,c,h,s,pos  
217034.000,0.000,0.000,45.000,-1.542614572,47.217689856,0,1  
217034.500,1662121746.081,0.500,43.762,-1.542614572,47.217689856,0,1  
217035.000,1662121747.877,0.500,45.000,-1.542614573,47.217689855,0,2  
217035.500,1662121749.670,0.500,45.000,-1.542614574,47.217689854,2,3  
...
```



### Evaluation criterion

The final metric will be based on the accuracy for the correct floor detection and the horizontal positioning error. In particular, the score for comparing the different location systems will be based on the following equations:

$$\text{Accuracy Score} = 3\text{rdQuartile}\{\text{SampleError}(R_i, E_i)\}, \forall \text{ groundtruth reference in all final test sets}$$

$$\text{SampleError}(R_i, E_i) = \text{Distance}(R_i, E_i) + (\text{penalty} \times \text{floorfail})$$

where:

- “3rdQuartile” is the third quartile error, in meters, of a cumulative error distribution function, i.e., the error value that includes 75% of estimations (sample errors) with a lower error.
- $R_i$  is the actual position (ground truth).
- $E_i$  is the predicted position estimate by the method proposed by the contest participant.
- floorfail is the absolute difference between actual floor and the predicted one.
- penalty is used to penalize errors in estimating the floor. penalty is set to 15 m.
- $\text{Distance}(R_i, E_i)$  calculates the Euclidean distance between coordinates (longitude and latitude) of  $R_i$  and  $E_i$ .

The team with the lower “Accuracy Score” wins.

### Contact points and information

For any further question about the database and this competition track, please contact to:

- Miguel Ortiz ([miguel.ortiz@univ-eiffel.fr](mailto:miguel.ortiz@univ-eiffel.fr)) at the University Gustave Eiffel, France.
- Ni Zhu ([ni.zhu@univ-eiffel.fr](mailto:ni.zhu@univ-eiffel.fr)) at the University Gustave Eiffel, France.

### Introduced changes

For any further question about the database and this competition track, please contact to:

Version 1.0	May 28 <sup>th</sup> , 2024	First version
Version 1.1	May 29 <sup>th</sup> , 2024	Final first version after internal review
Version 1.2	June 20 <sup>th</sup> , 2024	-Testing Trial inputs added -Ground Truth of TestingTrial will be given @60Hz for offline evaluation purpose. Only 32 ground truth key points will be given as POSI lines through EvaalAPI.
Version 1.3	July 20 <sup>th</sup> , 2024	Add information about a tutorial script for Testing Trial that can be used to help competitors to develop their own EvaalAPI script
<b>Version 1.4</b>	<b>Sept. 19<sup>th</sup>, 2024</b>	<b>-Application URL added</b> <b>- Scoring-1 Data added</b> <b>- Scoring-2 Data added</b>