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9.1 DDS PSM
9.2 GraphQL PSM
Preface

OMG

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Times/Times Roman - 10 pt.: Standard body text

Helvetica/Arial - 10 pt. Bold: OMG Interface Definition Language (OMG IDL) and syntax elements.


Helvetica/Arial - 10 pt: Exceptions

Command and Control Interface for Navigation (C2INav), v1.5
0 Issues To Be Discussed

0.1 Non-Function Quality of Service Requirements
a) Proposals shall discuss the non-functional, quality of service requirements typical in integration of navigation with C2 System systems, e.g. high levels of performance, latency and timing constraints, dependability and security.

Sensor Systems: accuracy and precision of attitude data is a major factor of the accuracy, precision and functional performance of the sensor in general. Also low latency is required for some types of sensor to accurately point the sensor or to steer its beam.

Effector Systems: dependability is required to mitigate the risks posed by systems designed to deliver an effect into the environment; also low latency and a predictive motion model is required to accurately deliver an effect from a platform experiencing translational and rotational acceleration in three dimensions.

Mission Critical Functions: require trusted information from an authenticated source.

The proposed C2INav data model scales to describe the information required for a broad range of mission critical applications – for instance the inclusion of time derivatives, accuracies and covariance at scalable compliance levels. The DDS PSM supports the latency, dependability, trust and authentication required for these critical functions through Quality of Service settings and the DDS Security standard.

0.2 Separation on a Shared Network
b) Discuss how the C2INAV can ensure data separation on a shared network (e.g. through the use of an access key associated with the data) from the Information Assurance point of view.

Data separation for Information Assurance can be achieved through the use of secure protocols in the PSM - e.g. DDS Security for the DDS PSM or HTTPS for the GraphQL PSM.

0.3 Configuration by a Client
c) Submitters should discuss how clients of the C2INAV can configure the C2INAV implementation to meet their specific needs. This covers such areas as (not an exhaustive list): Data update frequency, Data latency, Data reliability and Security.

The request_navigation_data method allows clients to configure data update frequency at the PIM level. Use of DDS PSM allows a client to configure data update frequency, data latency, data reliability and security.

0.4 Monotonic Data-streams
d) Submitters should discuss how the C2INAV shall either ensure that the data arrives in sequence (data monotonicity) or that the client of the C2INAV can determine that the data is not the latest value.

All reports from the Navigation System are time-stamped, this allows a client to determine whether a report is 'out-of-sequence' at the PIM level. For the DDS PSM, presentation quality of service settings can be used to specify ordering as required.

0.5 Security Protection from Cyber Threats
e) Submitters should discuss how the C2INAV implementations can be protected from security and cyber threats.

C2INAV implementations can be protected from security and cyber threats by using authentication, permission enforcing and encryption protocols in the PSMs such as Secure DDS and HTTPS.
Modular Data Model and Services separate information that potential has higher sensitivity (e.g. location), so protection may be applied with appropriate granularity.

1 Scope

This specification defines the interface between a Navigation System and Command and Control (C2) functions. It is concerned with the transfer of information regarding the location, movement, orientation and local environment of the platform of which the Navigation System is a part to C2 functions.

2 Conformance

This specification defines conformance points to promote both applicability and interoperability. Services within the specification relating to control of the information reported and specialist parts of the data model are optional. The mandatory services within the interface relate to the transfer of basic information with the default behavior of the Navigation System.

<table>
<thead>
<tr>
<th>Conformance Point</th>
<th>Data Model Packages</th>
<th>Service Methods</th>
<th>Rationale</th>
</tr>
</thead>
<tbody>
<tr>
<td>Basic Reporting</td>
<td>Navigation Domain, C2INav</td>
<td>write_rotational_attitude,</td>
<td>Supports a system where the most commonly used attributes are reported with the Navigation System's default behavior without any C2 control</td>
</tr>
<tr>
<td></td>
<td>Domain::Attitude,</td>
<td>write_velocity</td>
<td></td>
</tr>
<tr>
<td></td>
<td>Navigation Domain::Position</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Reporting Control</td>
<td>(Basic Reporting plus)</td>
<td>request_navigation_data</td>
<td>Supports a system where the C2 system can control the Navigation System's reporting of the most commonly used attributes</td>
</tr>
<tr>
<td></td>
<td>Navigation Domain::Reporting</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Specialist Data</td>
<td>All Packages</td>
<td>All Services</td>
<td>Supports the whole specification in the Navigation System's reporting of specialist data subject to control by the C2 System.</td>
</tr>
</tbody>
</table>

3 Normative References

The following normative documents contain provisions which, through reference in this text, constitute provisions of this specification. For dated references, subsequent amendments to, or revisions of, any of these publications do not apply:

- OARIS(formal/2016-03-02)
- DDS (formal/2015-04-10)
- IDL (formal/2018/01/05)
- EVOT (formal/2008-08-01)
- Network Time Protocol (www.ntp.org)
- Precision Time Protocol (IEEE 1588 – http://www.ieee1588.com)

4 Terms and Definitions

Command and Control Interface for Navigation (C2INav), v1.1
For the purposes of this specification, the following terms and definitions apply.

- **AB** (Architecture Board)
- **API** (Application Programming Interface)
- **BC** (Business Committee)
- **BCQ** (Business Committee Questionnaire)
- **BoD** (Board of Directors)
- **CCM** (CORBA Component Model)
- **CMS** (Combat Management System)
- **CORBA** (Common Object Request Broker Architecture)
- **CWM** (Common Warehouse Metamodel)
- **DAIS** (Data Acquisition from Industrial Systems)
- **DDS** (Data Distribution Service)
- **EVOT** (Enhanced View of Time)
- **FTF** (Finalization Task Force)
- **GLONASS** (Global Navigation Satellite System)
- **GPS** (Global Positioning System)
- **IDL** (Interface Definition Language)
- **IFF** (Interrogation, Friend or Foe)
- **IIOP** (Internet Inter-Orb Protocol)
- **IPR** (Intellectual Property Right)
- **ISO** (International Organization for Standardization)
- **LOI** (Letter of Intent)
- **LORAN** (Long Range Navigation)
- **MDA** (Model Driven Architecture)
- **METOC** (Meteorological and Oceanographic)
- **MOF** (Meta Object Facility)
- **MQS** (MQSeries)
- **NNSI** (Naval Navigation System Interface)
- **NS** (Naming Service)
- **OARIS** (Open Architecture Radar Interface Standard)
- **ODF** (Open Document Format)
- **OMG** (Object Management Group)
5 Symbols
No special symbols are introduced in this specification.

6 Additional Information

6.1 Acknowledgements
The following companies submitted this specification:
• BAE Systems
7 Command and Control Interface for Navigation Systems

7.1 Introduction
The specification is captured as an Enterprise Architect (EA) UML version 2.1 model; this document being automatically generated as a report from the model.

The UML model is an extension of the OARIS model and follows the same hierarchical structure and naming conventions; this model also has dependencies on the Common Types package defined by the OARIS model (as shown in Figure 7.1) as it reuses classes defined there. The classes re-used from the OARIS specification are shown on the class diagrams for the Domain Model. The general purpose error handling service classes defined by OARIS are also re-used.

The C2INav model follows the OARIS model organization: there is a UML PIM data model (Navigation_Domain) under the Domain_Model package and a UML PIM for services and interfaces (Navigation_Services) under the Service_Interfaces package. The data model is organized by primary concerns for navigation information, for instance attitude or orientation versus absolute location in the environment, and also models the means of controlling reporting by a navigation system; a common abstraction for reporting is also modelled. The services and their interfaces model the means for a navigation system to report its data and a C2 system to control the characteristics of the navigation system’s reporting.

Additionally OARIS service interfaces defined for the Provide Subsystem Identification and Manage Subsystem Parameters use cases can be used by C2 Systems to discover and configure a Navigation System. (E.g. choose to listen to a specific Navigation System having been informed of its latency and granularity characteristics).

C2INav follows OARIS modelling nomenclature whereby there are interfaces conceptually representing a CMS and a Subsystem for each use case. For C2INav, CMS should be read as representative of C2 Systems in general and Subsystem as being specifically a Navigation System.

7.2 Navigation_Domain
Parent Package: Domain_Model
This package contains the Domain Models for the Navigation services. It is organised according to functionality: i.e. the modelling of attitude (the orientation and offset of the platform relative to its reported position), the platform's position (including velocity and acceleration), the depth of water the platform may be in and the reporting of this information.

Figure 7.1 Navigation (Package diagram)
7.2.1 accuracy_derivation_type

**Type:** IDLEnum  
**Package:** Navigation_Domain

The set of methods describing the provenance of the accuracy values

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>«idlEnum» DYNAMICALY_CALIBRATED</td>
<td>The accuracy values have been calibrated using real data to derive accuracy values for particular instruments given particular environmental conditions - i.e. accuracy values will in general vary over time for the same set of instruments.</td>
</tr>
<tr>
<td>«idlEnum» ESTIMATED</td>
<td>The values have been set using engineering judgement.</td>
</tr>
<tr>
<td>«idlEnum» MEASURED</td>
<td>The accuracy values have been measured using some dynamic process that is able to estimate the current performance of the instruments in use.</td>
</tr>
<tr>
<td>«idlEnum» STATICALLY_CALIBRATED</td>
<td>The accuracy values have been calibrated using real data to derive fixed accuracy values for particular instruments.</td>
</tr>
</tbody>
</table>

7.2.2 navigation_accuracy_type

**Type:** IDLStruct  
**Package:** Navigation_Domain

A base type for classes that report the accuracy of navigational measurements

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>derivation accuracy_derivation_type</td>
<td>The provenance or method by which the accuracy values have been derived.</td>
</tr>
<tr>
<td>time_accuracy duration_type</td>
<td>The accuracy (represented as one standard deviation) of the time value.</td>
</tr>
</tbody>
</table>
7.2.3 navigation_derivation_kind_type
Type: IDLEnum
Package: Navigation_Domain
This is the set of instrument types and other means by which navigation information can be derived.

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>«idlEnum» COMPOSITE</td>
<td>Information derived by fusing data from more than one of these types of derivation source.</td>
</tr>
<tr>
<td>«idlEnum» DENSITY_SENSOR</td>
<td>Information derived from an instrument that measures the (subsurface) sea or air density to estimate depth or altitude.</td>
</tr>
<tr>
<td>«idlEnum» DOPPLER_LOG</td>
<td>Information derived from an instrument that exploits the Doppler effect to measure speed relative to the immediate environment, particularly water.</td>
</tr>
<tr>
<td>«idlEnum» EM_LOG</td>
<td>Information derived from an instrument that exploits the electromagnetic dynamo effect (conductor moving through an electromagnetic field produces a proportional voltage) to measure speed relative to the immediate environment, particularly water.</td>
</tr>
<tr>
<td>«idlEnum» ESTIMATED</td>
<td>Information is estimated from previously measured values (e.g. dead-reckoning).</td>
</tr>
<tr>
<td>«idlEnum» INS</td>
<td>Information derived from instruments based on an Inertial Navigation System (e.g. Gyroscopes and Accelerometers)</td>
</tr>
<tr>
<td>«idlEnum» LW_HYPERBOLIC_INTERSECT</td>
<td>Navigation based on the intersection of hyperbolic curves derived from long wave radio signals from known ground stations with repeaters - e.g. LORAN B and C</td>
</tr>
<tr>
<td>«idlEnum» OTHER_METHOD</td>
<td>Information has been derived using some other technology</td>
</tr>
<tr>
<td>«idlEnum» PRESSURE_SENSOR</td>
<td>Information derived from an instrument that measures the (subsurface) sea or air pressure to estimate depth or altitude.</td>
</tr>
<tr>
<td>«idlEnum» QUANTUM_GEOLOCATION</td>
<td>Information derived by sensing the Earth’s gravitational and/or magnetic field and/or their gradients using single particle systems that exploit quantum effects.</td>
</tr>
<tr>
<td>«idlEnum» QUANTUM_INS</td>
<td>Information derived from instruments based on an Inertial Navigation System that measures acceleration using single particle systems that exploit quantum techniques.</td>
</tr>
<tr>
<td>«idlEnum» SATELLITE</td>
<td>Information derived from a satellite-based navigation system (e.g. GPS and GLONASS)</td>
</tr>
<tr>
<td>«idlEnum» USER_SUPPLIED</td>
<td>Information has been supplied by the user (e.g. manual entry from a non-integrated system).</td>
</tr>
<tr>
<td>«idlEnum» VISUAL_GEOLOCATION</td>
<td>Information derived by sensing the external environment and resolving position and orientation with reference to external data such as charts (e.g. SLAM techniques).</td>
</tr>
</tbody>
</table>

7.2.4 Attitude
Parent Package: Navigation_Domain
This package contains classes to model the attitude of the platform. That is the orientation and offset of the platform relative to its reported position. This package provides a data model for services that relate to micro-scale precision, supporting precise location and orientation of an individual component of the
7.2.4.1 attitude_rotation_accuracy_type
Type: IDLStruct navigation_accuracy_type
Package: Attitude
This class encapsulates the error estimates associated with the platform’s rotational attitude values.
Accuracies are reported as one standard deviation.

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>pitch_accuracy</td>
<td>The accuracy of the pitch value to one standard deviation,</td>
</tr>
<tr>
<td>roll_accuracy</td>
<td>The accuracy of the roll value to one standard deviation,</td>
</tr>
<tr>
<td>yaw_accuracy</td>
<td>The accuracy of the yaw value to one standard deviation,</td>
</tr>
</tbody>
</table>

7.2.4.2 attitude_rotation_type
Type: IDLStruct offset_report_type
**Package:** Attitude
This class encapsulates the instantaneous rotation of the platform from its nominal, at-rest orientation. Non-normative: typically due to the variable motion of the environment - sea, air, etc. - through which it is travelling.

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>pitch</strong> elevation_coordinate_type</td>
<td>The pitch of the platform, relative to its platform reference point in a vertical plane. It is the clockwise angle of rotation around the lateral axis (towards starboard/right) through the center of rotation. For sea systems, the angle from horizontal to the bow; for air systems, the angle from horizontal to the nose; for land systems, the angle from horizontal to the front.</td>
</tr>
<tr>
<td><strong>roll</strong> elevation_coordinate_type</td>
<td>The roll of the platform, relative to its platform reference point in a vertical plane. It is the angle of rotation about the longitudinal axis through the center of rotation (front-to-back). The roll angle is defined as that of the at-rest horizontal through the platform's reference on the starboard side for sea and air systems and on the right (forward facing) for land systems.</td>
</tr>
<tr>
<td><strong>yaw</strong> azimuth_coordinate_type</td>
<td>The yaw of the platform, relative to its platform reference point in a horizontal plane. It is the angle of rotation about the vertical axis through the center of rotation (top-to-bottom) relative to the platform's course. For sea systems, the angle to the bow; for air systems, the angle to the nose; for land systems, the angle to the front.</td>
</tr>
</tbody>
</table>

### 7.2.4.3 measurement_kind_type

**Type:** IDLEnum

**Package:** Attitude

The kind of measurement relating to the statistical process applied to the quantities in question over time.

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>«idlEnum» ABSOLUTE_PEAK</td>
<td>The maximum of the absolute value of the raw measurements over a complete cycle (a complete cycle is defined as the interval between local maxima).</td>
</tr>
<tr>
<td>«idlEnum» INSTANTANEOUS</td>
<td>The raw measurement at the stated time</td>
</tr>
<tr>
<td>«idlEnum» MEAN</td>
<td>The arithmetic mean (average) of the raw measurements over a complete cycle (a complete cycle is defined as the interval between local maxima).</td>
</tr>
<tr>
<td>«idlEnum» ROOT_MEAN_SQUARE</td>
<td>The root mean square average of the raw measurements over a complete cycle (a complete cycle is defined as the interval between local maxima).</td>
</tr>
<tr>
<td>«idlEnum» SMOOTHED</td>
<td>The system's best estimate for the current value of the quantities based on recent raw measurements.</td>
</tr>
</tbody>
</table>

### 7.2.4.4 offset_report_type

**Type:** IDLStruct navigation_report_type

**Package:** Attitude

This is the base type for the reporting of all information that is an offset from the platform's mean reported
motion and its at-rest orientation; hence this includes attitude information. These reports are keyed on the statistical kind of measurement, enabling different views of cyclical motion to be reported.

Table 7.7- Attributes of IDLStruct offset_report_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>«key» measurement_kind</td>
<td>measurement_kind_type</td>
</tr>
</tbody>
</table>

7.2.4.5 Attitude Ext

Parent Package: Attitude

Figure 7.4 Attitude Ext (Logical diagram)

7.2.4.5.1 attitude_rotation_rate_accuracy_type

Type: IDLStruct navigation_accuracy_type

Package: Ext

This class encapsulates the error estimates associated with the platform’s rotational attitude rate values. Accuracies are reported as one standard deviation.
Table 7.8 - Attributes of IDLStruct attitude_rotation_rate_accuracy_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>pitch_rate_accuracy</td>
<td>The accuracy of the pitch rate value to one standard deviation,</td>
</tr>
<tr>
<td>roll_rate_accuracy</td>
<td>The accuracy of the roll rate value to one standard deviation,</td>
</tr>
<tr>
<td>yaw_rate_accuracy</td>
<td>The accuracy of the yaw rate value to one standard deviation,</td>
</tr>
</tbody>
</table>

7.2.4.5.2 attitude_rotation_rate_type

Type: IDLStruct offset_report_type
Package: Ext
This class encapsulates the instantaneous rate of rotation of the platform (relative to the Earth).

Table 7.9 - Attributes of IDLStruct attitude_rotation_rate_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>pitch_rate elevation_rate_type</td>
<td>The pitch rate of the platform, relative to its platform reference point in a vertical plane. It is the rate of change of angle of rotation around the lateral axis (towards starboard/right) through the center of rotation. For sea systems, the angle to the bow; for air systems, the angle to the nose; for land systems, the angle to the front.</td>
</tr>
<tr>
<td>roll_rate elevation_rate_type</td>
<td>The roll rate of the platform, relative to its platform reference point in a vertical plane. It is the rate of change of angle of rotation about the longitudinal axis through the center of rotation (front-to-back). The roll angle is defined as that of the at-rest horizontal through the platform's reference on the starboard side for sea and air systems and on the right (forward facing) for land systems.</td>
</tr>
<tr>
<td>yaw_rate azimuth_rate_type</td>
<td>The yaw rate of the platform, relative to its platform reference point in a horizontal plane. It is the rate of change of the angle of rotation about the vertical axis through the center of rotation (top-to-bottom) relative to the platform’s course. For sea systems, the angle to the bow; for air systems, the angle to the nose; for land systems, the angle to the front.</td>
</tr>
</tbody>
</table>

7.2.4.5.3 position_offset_accuracy_type

Type: IDLStruct navigation_accuracy_type
Package: Ext
This class encapsulates the error estimates associated with the platform's attitude offset values. Accuracies are reported as one standard deviation.

Table 7.10 - Attributes of IDLStruct position_offset_accuracy_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>sway_accuracy</td>
<td>The accuracy of the lateral value to one standard deviation,</td>
</tr>
<tr>
<td>surge_accuracy</td>
<td>The accuracy of the longitudinal value to one standard deviation,</td>
</tr>
<tr>
<td>heave_accuracy</td>
<td>The accuracy of the vertical value to one standard deviation,</td>
</tr>
</tbody>
</table>
7.2.4.5.4  position_offset_type
Type: IDLStruct offset_report_type
Package: Ext
This class encapsulates the instantaneous offset of the platform from its mean reported motion.
Non-normative: typically due to the variable motion of the environment - sea, air, etc. - through which it is travelling.

Table 7.11 - Attributes of IDLStruct position_offset_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>sway cartesian_coordinate_type</td>
<td>The instantaneous offset from mean motion on the lateral horizontal axis through the platform reference point. For sea and air systems port-starboard - starboard positive For land systems side-to-side - right positive when facing forwards.</td>
</tr>
<tr>
<td>surge cartesian_coordinate_type</td>
<td>The instantaneous offset from mean motion on the longitudinal horizontal axis through the platform reference point. For sea systems stern-bow - bow positive For air systems tail-nose - nose positive For land systems back-to-front - front positive.</td>
</tr>
<tr>
<td>heave cartesian_coordinate_type</td>
<td>The instantaneous offset from mean motion on the vertical axis through the platform reference point. For sea systems keel-mast - mast positive For air and land systems bottom-to-top - top positive.</td>
</tr>
</tbody>
</table>

7.2.4.5.5  velocity_offset_accuracy_type
Type: IDLStruct navigation_accuracy_type
Package: Ext
This class encapsulates the error estimates associated with the platform's attitude offset rate values.
Accuracies are reported as one standard deviation.

Table 7.12 - Attributes of IDLStruct velocity_offset_accuracy_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>sway_rate_accuracy cartesian_velocity_component_type</td>
<td>The accuracy of the lateral rate value to one standard deviation,</td>
</tr>
<tr>
<td>surge_rate_accuracy cartesian_velocity_component_type</td>
<td>The accuracy of the longitudinal rate value to one standard deviation,</td>
</tr>
<tr>
<td>heave_rate_accuracy cartesian_velocity_component_type</td>
<td>The accuracy of the vertical rate value to one standard deviation,</td>
</tr>
</tbody>
</table>

7.2.4.5.6  velocity_offset_type
Type: IDLStruct offset_report_type
Package: Ext
This class encapsulates the instantaneous rate of change of the offset of the platform from its mean reported motion.

Table 7.13 - Attributes of IDLStruct velocity_offset_type
<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>sway_rate</td>
<td>The instantaneous rate of change of the offset from mean motion on the lateral horizontal axis through the platform reference point. For sea and air systems port-starboard - starboard positive. For land systems side-to-side - right positive when facing forwards.</td>
</tr>
<tr>
<td>surge_rate</td>
<td>The instantaneous rate of change of the offset from mean motion on the longitudinal horizontal axis through the platform reference point. For sea systems stern-bow - bow positive. For air systems tail-nose - nose positive. For land systems back-to-front - front positive.</td>
</tr>
<tr>
<td>heave_rate</td>
<td>The instantaneous rate of change of the offset from mean motion on the vertical axis through the platform reference point. For sea systems keel-mast - mast positive. For air and land systems bottom-to-top - top positive.</td>
</tr>
</tbody>
</table>

7.2.5 Depth

Parent Package: Navigation_Domain

This package contains classes to model the depth of water the platform may be in.

![Figure 7.5 Depth (Logical diagram)](image)

7.2.5.1 depth_coordinate_type

Type: IDLTypeDef double

Package: Depth

Measured positive down in meters. c.f. altitude_coordinate_type in OARIS Common_Types package.

Range = -1e2 .. 1e5

Unit = m
Resolution = 1
Unit = m

7.2.5.2 depth_report_type
Type: IDLStruct
Package: Depth
Used by waterborne craft to report depth information.

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>depth_below_keel depth_coordinate_type [0..1]</td>
<td>The depth of the bed below the keel.</td>
</tr>
<tr>
<td>keel_depth depth_coordinate_type [0..1]</td>
<td>The depth of the keel below the surface of the water.</td>
</tr>
<tr>
<td>water_depth depth_coordinate_type [0..1]</td>
<td>The depth of the bed below the water's surface.</td>
</tr>
</tbody>
</table>

7.2.5.3 depth_accuracy_type
Type: IDLStruct
Package: Depth
The accuracy of the platform's depth report

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>depth_below_keel depth_coordinate_type [0..1]</td>
<td>The accuracy of the depth below keel measurement.</td>
</tr>
<tr>
<td>keel_depth depth_coordinate_type [0..1]</td>
<td>The accuracy of the keel depth measurement.</td>
</tr>
<tr>
<td>water_depth depth_coordinate_type [0..1]</td>
<td>The accuracy of the water depth measurement.</td>
</tr>
</tbody>
</table>

7.2.6 Position
Parent Package: Navigation_Domain
This package contains classes to model the platform's position including height/depth/altitude, velocity and acceleration. This package provides a data model for services that relate to macro-scale precision, supporting the location and motion of the platform as a point entity within its environment.
7.2.6.1 altitude_measurement_type

Type: IDLEnum

Package: Position

This class indicates the semantics of the height attribute. It describes how the reported height (or depth) has been derived.

Table 7.16 - Attributes of IDLEnum altitude_measurement_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>»enum DENSITY</td>
<td>It is reporting a measurement based on local density (of air or water).</td>
</tr>
<tr>
<td>»enum GRAVITY</td>
<td>It is reporting a measurement based on local gravity.</td>
</tr>
</tbody>
</table>

Command and Control Interface for Navigation (C2INav), v1.1
### own_position_accuracy_type

**Type:** IDLStruct navigation_accuracy_type  
**Package:** Position

The accuracy of the platform's own position report.

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>position_accuracy_coordinate_type</td>
<td>The accuracy of the reported position in the chosen coordinate system for reporting. This should be the same choice as for the position itself.</td>
</tr>
</tbody>
</table>

### own_position_type

**Type:** IDLStruct navigation_report_type  
**Package:** Position

The platform's own position report.

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>altitude_kind</td>
<td>altitude_measurement_type [0..1] Describes the semantics of the position's altitude attribute. Optional: omit only if altitude is not reported.</td>
</tr>
<tr>
<td>coordinate_specification</td>
<td>coordinate_specification_type The specification of the coordinate system used for reporting own position and its accuracy. In most use cases Cartesian or WGS84, Earth Referenced choices are expected; in some use cases other choices for reporting relative to some known datum could be used.</td>
</tr>
<tr>
<td>position</td>
<td>position_coordinate_type The position of the reporting platform in the chosen coordinate system for reporting.</td>
</tr>
</tbody>
</table>

### own_velocity_accuracy_type

**Type:** IDLStruct navigation_accuracy_type  
**Package:** Position

The accuracy of the platform's own velocity report.

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>velocity</td>
<td>velocity_accuracy_coordinate_type The accuracy of the reporting platform's velocity with reference to the coordinate system used for reporting.</td>
</tr>
</tbody>
</table>

### own_velocity_type

**Type:** IDLStruct navigation_report_type
Package: Position
The platform's own velocity report.

Table 7.20 - Attributes of IDLStruct own_velocity_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>coordinate_specification</td>
<td>The specification of the coordinate system used for reporting own velocity and its accuracy. In most use cases Cartesian or WGS84, Earth Referenced choices are expected; in some use cases other choices for reporting relative to some known datum could be used.</td>
</tr>
<tr>
<td>coordinate_specification_type</td>
<td></td>
</tr>
<tr>
<td>measurement_kind</td>
<td>The definition of the velocity being measured.</td>
</tr>
<tr>
<td>velocity</td>
<td>The velocity of the reporting platform with reference to the chosen coordinate system for reporting.</td>
</tr>
<tr>
<td>velocity_coordinate_type</td>
<td></td>
</tr>
</tbody>
</table>

7.2.6.6 velocity_measurement_type

Type: IDLEnum
Package: Position
This class defines what it is that is having its velocity measured.

Table 7.21 - Attributes of IDLEnum velocity_measurement_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>ABSOLUTE</td>
<td>The measurement is of absolute velocity (i.e. relative to the Earth).</td>
</tr>
<tr>
<td>AIR</td>
<td>The measurement is of the air in the local environment itself (i.e. the wind speed). This is only to be reported as a true value; i.e. it is not based on a pressure-based 'indicated' sensor reading for relative air speed that isn't corrected for density.</td>
</tr>
<tr>
<td>RELATIVE_INDICATED</td>
<td>The measurement is of velocity relative to the environment (i.e. water or air) using an indirect approximation such as air pressure.</td>
</tr>
<tr>
<td>RELATIVE_TRUE</td>
<td>The measurement is of velocity relative to the environment (i.e. water or air) using a method that is not subject to systematic approximation error as is the case with 'Indicated Air Speed' as measured by a pressure sensor.</td>
</tr>
<tr>
<td>WATER</td>
<td>The measurement is of the water current in the local environment itself (i.e. the movement of the water).</td>
</tr>
</tbody>
</table>

7.2.6.7 Position.Ext

Parent Package: Position
7.2.6.7.1 \textit{own\_acceleration\_accuracy\_type}

Type: IDLStruct
Package: Ext

The accuracy of the platform's own acceleration report.

Table 7.22 - Attributes of IDLStruct own\_acceleration\_accuracy\_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>\textit{angle_of_climb_rate_accuracy}</td>
<td>elevation_rate_type [0..1] - 1 standard deviation</td>
</tr>
<tr>
<td>\textit{heading_rate_accuracy}</td>
<td>azimuth_rate_type - 1 standard deviation</td>
</tr>
<tr>
<td>\textit{speed_rate_accuracy}</td>
<td>speed_rate_type - 1 standard deviation</td>
</tr>
</tbody>
</table>

7.2.6.7.2 \textit{own\_acceleration\_type}

Type: IDLStruct navigation\_report\_type
Package: Ext

The platform's reporting of its change in velocity

Table 7.23 - Attributes of IDLStruct own\_acceleration\_type

Command and Control Interface for Navigation (C2INav), v1.5
<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>angle_of_climb_rate</td>
<td>The rate at which the angle of climb is changing</td>
</tr>
<tr>
<td>heading_rate</td>
<td>The rate at which the heading is changing</td>
</tr>
<tr>
<td>measurement_kind</td>
<td>The definition of the acceleration (change in velocity) being measured.</td>
</tr>
<tr>
<td>speed_rate</td>
<td>The rate at which the speed is changing</td>
</tr>
</tbody>
</table>

7.2.6.7.3 speed_rate_type
Type: IDLTypeDef double
Package: Ext
The rate of change of speed in meters per second-squared
Range = \(-1e3 \ldots 1e3\)
Resolution = 0.001
Unit = m/s²

7.2.7 Reporting
Parent Package: Navigation_Domain
This package contains classes that provide a common abstraction for the reporting of navigation information.

![Figure 7.8 Reporting (Logical diagram)](image)

7.2.7.1 navigation_report_kind_type
Type: IDLTypeDef implementation defined
Package: Reporting
This class is used in service selection to specify the type of navigation report being requested. Its implementation is determined by the PSM mapping.

7.2.7.2 navigation_report_type
Type: IDLStruct
Package: Reporting
A base type for classes that report navigational measurements

<table>
<thead>
<tr>
<th>Table 7.24 - Attributes of IDLStruct navigation_report_type</th>
</tr>
</thead>
</table>

Command and Control Interface for Navigation (C2INav), v1.1
7.2.7.3 Reporting.Ext

Parent Package: Reporting

Figure 7.9 Reporting Ext (Logical diagram)

7.2.7.3.1 navigation_covariance_type
Type: IDLStruct
Package: Ext
This class encapsulates the covariance between the measurements in one or more navigation_report_instances. The rows and columns of the triangular covariance matrix relate to the (3) quantities from the first instance, optionally the (3) quantities from each of the further instances and finally, optionally, time.
This, for instance allows the covariance between rotational attitude and position to be represented or the covariance between rotational attitude, position, all their rates of change and time.

Table 7.15 - Attributes of IDLStruct navigation_covariance_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>include_time</td>
<td>Whether time is included in the covariance - it is always represented in the last row and column.</td>
</tr>
</tbody>
</table>
7.2.7.3.2 navigation_report_kind_sequence_type

**Type:** IDLSequence navigation_report_kind_type  
**Package:** Ext  
A sequence of navigation report kinds. It is expected that this class will map to implementation specific mechanisms in PSMs.

### Table 7.6 - Attributes of IDLStruct navigation_request_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>value double [0..*]</td>
<td>The content of the triangular covariance matrix omitting symmetric (duplicate) values. Valid lengths are ( \text{sum}(n=1..<em>; 3n) ) and ( \text{sum}(n=1..</em>; 3n+1) ). The sequence starts 6, 10, 21, 28, 45, ...</td>
</tr>
</tbody>
</table>

7.2.8 Reporting

**Parent Package:** Navigation_Domain  
This package contains classes that encapsulate the information that can parameterize the reporting of navigation information.

**Class Requests**

```
<idlStruct>
  navigation_request_type
  + report_kind: navigation_report_kind_type
  + measurement_kind: measurement_kind_type [0..1]
  + velocity_measurement: velocity_measurement_type [0..1]
  + interval: duration_type [0..1]
</idlStruct>
```

Figure 7.10 Requests (Logical diagram)

7.2.8.1 navigation_request_type

**Type:** IDLStruct  
**Package:** Reporting  
This class is used to construct requests for data to a navigation system and also to cancel such requests. When used to cancel requests the interval should be omitted by the C2 System and ignored by the Navigation System.

### Table 7.6 - Attributes of IDLStruct navigation_request_type

<table>
<thead>
<tr>
<th>Attribute</th>
<th>Notes</th>
</tr>
</thead>
<tbody>
<tr>
<td>interval duration_type [0..1]</td>
<td>The nominal interval between reports being requested. Omit to request at the default rate for the navigation system.</td>
</tr>
<tr>
<td>measurement_kind measurement_kind_type [0..1]</td>
<td>The kind of statistical reporting of the measurements being requested. Omit to request all measurement kinds supported by the navigation system.</td>
</tr>
<tr>
<td>report_kind navigation_report_kind_type</td>
<td>The type of data to be reported in response to the request.</td>
</tr>
<tr>
<td>velocity_measurement velocity_measurement_type [0..1]</td>
<td>The type of velocity measurement requested. This is only valid if the report kind indicates velocity. Omit to request all velocity measurements supported by the navigation system.</td>
</tr>
</tbody>
</table>

7.3 Navigation_Services

**Parent Package:** Service_Interfaces  
The Navigation Services define the methods for a Navigation System to report its data to a C2 System.

Command and Control Interface for Navigation (C2INav), v1.1
and for a C2 System to control the rate and content of the data reported by a Navigation System. The usage of these services is presented in a series of sequence diagrams aligned with this specification’s conformance points from section 2; basic flows describe normal operation and alternative flows describe error handling.

Navigation_CMS and Navigation_Sub are the interfaces to be implemented by C2 (including CMS) and Navigation System components respectively.

![Sequence diagram](image)
This illustrates the expected interaction between the C2 System and Navigation System for the C2INav Reporting Control conformance point.

- **At default rate**
  - `write_attitude_offset(position_offset_type)`
  - `write_attitude_offset_rate(velocity_offset_type)`
  - `write_rotational_attitude(attitude_rotation_type)`
  - `write_acceleration(own_acceleration_type)`
  - `write_velocity(own_velocity_type)`

- **Position**
  - `loop for each position reporting interval`
  - `loop for each attitude reporting interval`
  - `write_position(own_position_type)`
  - `write_velocity(own_velocity_type)`
  - `write_rotational_attitude_rate(attitude_rotation_rate_type)`

- **At default rate**
  - `receive_acknowledgement(request_id_type, request_ack_type)`
  - `request_default_navigation_data(request_id, cancel=true)`

Figure 7.12 Basic Flow - Reporting Control - Default (Sequence diagram)
This illustrates the expected interaction between the C2 System and Navigation System for the C2INav Reporting Control conformance point, where specialist data is required.

```
request_custom_navigation_data(request_id, report_kind=own_position, position_kind=relative, cancel=false)
```

```
write_position(own_position_type)
```

```
request_custom_navigation_data(request_id, report_kind=velocity, velocity_kind=AIR, interval=air_velocity_interval, cancel=false)
```

```
write_velocity(air_velocity)
```

```
request_custom_navigation_data(request_id, report_kind=velocity, velocity_kind=RELATIVE, interval=relative_velocity_interval, cancel=false)
```

```
write_velocity(relative_velocity)
```

```
request_custom_navigation_data(request_id, report_kind=rotational_attitude, rotation_kind=RMS, cancel=true)
```

```
write_rotational_attitude(rotation_rotation_type)
```

```
request_custom_navigation_data(request_id, report_kind=rotational_attitude, rotation_kind=ROTATIONAL, cancel=false)
```

```
write_rotation(own_rotation_attitude)
```

```
request_custom_navigation_data(request_id, report_kind=position, position_kind=DOPPLER, interval=position_interval, cancel=false)
```

```
write_position(position_position_type)
```

```
request_custom_navigation_data(request_id, report_kind=position, position_kind=DOPPLER, interval=relative_velocity_interval, cancel=false)
```

```
write_position(position_position_type)
```

```
request_custom_navigation_data(request_id, report_kind=velocity, velocity_kind=AIR, interval=air_velocity_interval, cancel=false)
```

```
write_velocity(air_velocity)
```

```
request_custom_navigation_data(request_id, report_kind=velocity, velocity_kind=DOPPLER, interval=relative_velocity_interval, cancel=false)
```

```
write_velocity(relative_velocity)
```
This illustrates the expected interaction between the C2 System and Navigation System for the C2INav Specialist Data conformance point.

Figure 7.13 Basic Flow - Reporting Control - Specific (Sequence diagram)

```
loop for each reporting interval
[At default rate]
write_attitude_rotation(attitude_rotation_type)
write_attitude_offset(position_offset_type)
write_position(own_position_type)
write_covariance(navigation_covariance_type)

request_covariance(request_id, {rotational_attitude, attitude_offset, position}, cancel=true)
receive_acknowledgement(request_id_type, request_ack_type)

request_custom_navigation_data(request_id, report_kind=position, cancel=false)
receive_acknowledgement(request_id_type, request_ack_type)

request_custom_navigation_data(request_id, report_kind=rotational_attitude, cancel=false)
receive_acknowledgement(request_id_type, request_ack_type)

request_custom_navigation_data(request_id, report_kind=attitude_offset, cancel=false)
receive_acknowledgement(request_id_type, request_ack_type)
```

Figure 7.14 Basic Flow - Specialist Data - Covariance (Sequence diagram)
This illustrates an error producing interaction between the C2 System and Navigation System for the C2INav Reporting Control conformance point. The Navigation System is unable to provide the specifically requested data.

```
request_custom_navigation_data(request_id, report_kind=velocity_measurement_kind=PEAK, cancel=false)
receive_acknowledgement(request_id, accepted=false)
receive_error(request_id, measurement_kind_not_supported)
request_custom_navigation_data(request_id, report_kind=position_interval=position_interval, cancel=false)
receive_acknowledgement(request_id, accepted=false)
receive_error(request_id, interval_not_supported)
request_custom_navigation_data(request_id, report_kind=rotational_attitude, cancel=false)
receive_error(request_id, report_kind_not_supported)
```

This illustrates an error producing interaction between the C2 System and Navigation System for the C2INav Specialist Data conformance point. The Navigation System is unable to provide the specifically requested covariance data.

```
request_default_navigation_data(requets_id, cancel=false)
receive_acknowledgement(request_id, accepted=false)
request_covariance(request_id, {rotational_attitude_rate, acceleration})
receive_acknowledgement(request_id, accepted=true)
request_covariance(request_id, {rotational_attitude_rate, acceleration})
receive_error(request_id, covariance_variables_not_supported)
```
7.3.1 Navigation_CMS

**Type:** IDLInterface common_use_case_interface

**Package:** Navigation_Services

The interface implemented by C2 components to consume C2INav services

### Table 7.27 - Methods of IDLInterface Navigation_CMS

<table>
<thead>
<tr>
<th>Method</th>
<th>Notes</th>
<th>Parameters</th>
</tr>
</thead>
<tbody>
<tr>
<td>write_acceleration()</td>
<td></td>
<td>own_acceleration_type acceleration</td>
</tr>
<tr>
<td>write_attitude_offset()</td>
<td></td>
<td>position_offset_type offset</td>
</tr>
<tr>
<td>write_attitude_offset_rate()</td>
<td></td>
<td>velocity_offset_type rate</td>
</tr>
<tr>
<td>write_covariance()</td>
<td>The reported covariance between the selected quantities.</td>
<td>navigation_covariance_type covariance</td>
</tr>
<tr>
<td>write_depth()</td>
<td></td>
<td>depth_report_type depth</td>
</tr>
<tr>
<td>write_position()</td>
<td></td>
<td>own_position_type position</td>
</tr>
<tr>
<td>write_rotational_attitude()</td>
<td></td>
<td>attitude_rotation_type rotation</td>
</tr>
<tr>
<td>write_rotational_attitude_rate()</td>
<td></td>
<td>attitude_rotation_rate_type rate</td>
</tr>
<tr>
<td>write_velocity()</td>
<td></td>
<td>own_velocity_type velocity</td>
</tr>
</tbody>
</table>

7.3.2 Navigation_Sub

**Type:** IDLInterface

**Package:** Navigation_Services

Command and Control Interface for Navigation (C2INav), v1.1
The interface implemented by a navigation system to provide C2INav services.

<table>
<thead>
<tr>
<th>Method</th>
<th>Notes</th>
<th>Parameters</th>
</tr>
</thead>
<tbody>
<tr>
<td>request_covariance()</td>
<td>Requests the covariance between a chosen set of quantities to be reported. The covariance is to be reported at the fastest reporting rate of the chosen quantities. Can also cancel requests to the navigation system to send the particular covariance information.</td>
<td>request_id_type request_id navigation_report_kind_sequence_type report_kinds boolean cancel</td>
</tr>
<tr>
<td>request_default_navigation_data()</td>
<td>Request the navigation system to send all its available navigational information at the navigation system's default rate for the data. Where the reported data can have different statistical representations (measurement kinds) all forms supported by the navigation subsystem are reported at the navigation system's default rate for that measurement and report kind. Can also cancel requests to the navigation system to send any of its available navigational information.</td>
<td>request_id_type request_id boolean cancel</td>
</tr>
<tr>
<td>request_custom_navigation_data()</td>
<td>Request the navigation system to send a particular kind of navigation report with specified measurement types at a configurable interval. If the data is already being reported then this request updates the interval at which it is reported (or sets it to the navigation system's default rate); it does not act cumulatively on existing data reporting. Can also cancel requests to the navigation system to send any of its available navigational information.</td>
<td>request_id_type request_id navigation_request_type request boolean cancel</td>
</tr>
</tbody>
</table>
8 Domain Model Platform-Specific Models

8.1 DDS PSM
The DDS Data Model PSM defines a set of IDL files for the Data Model packages defined by the PIM. Topic types (i.e. IDL structs with keys) are defined for those IDL struct stereotyped classes that classify a single parameter on an interface method. This avoids redundant indirection. Comments are added to the IDL files to reflect the mapping rules below.

IDL types referred to by this PSM but defined by OARIS are to be found in the DDS PSM files for the OARIS specification. This specification depends upon Common_Types.idl, Coordinates_and_Positions.idl and TimeBase.idl.

The detailed rules for the MDA code generation from the Data Model PIM to the DDS PSM IDL are as follows:

- The PIM attributes are mapped to IDL attributes;
- Optional attributes are mapped to a union type with a single member present when the exists case attribute is true;
- Collections in the PIM are mapped to IDL sequences;
- Specialization / Generalization PIM relationships are mapped to in-lined base type attributes
- Navigable association to topic instance types are mapped to a key value, or set of values defined by a struct, where there are multiple keys. Where the association is to a generalization a union of the possible key types of the specializations is used. Unions and supporting enumerations are defined irrespective of the existence of associations to use them. One-to-many associations map to a bounded sequence of such values.

8.2 GraphQL PSM
The GraphQL Data Model PSM defines a single combined schema file for the Data Model and Service Model defined by the PIM.

The detailed rules for the MDA code generation from the Data Model PIM to the DDS PSM IDL are as follows:

- The PIM attributes are mapped to GraphQL type attributes;
- Mandatory attributes are mapped to a mandatory GraphQL attributes with an exclamation mark – ‘!’;
- Optional attributes are mapped to a optional GraphQL attributes without an exclamation mark
- Collections in the PIM are mapped to GraphQL sequences;
- Aggregation and compositions are mapped to GraphQL attributes;
- Specialization / Generalization PIM relationships are mapped to IDL unions. Generalization classes that have attributes are mapped to a GraphQL type containing a base GraphQL type for its common attributes and a variants union for the specialization attributes.
- Navigable associations to topic instance types are mapped to a key value, or set of values defined by a GraphQL type, where there are multiple keys. Where the association is to a generalization a union of the possible key types of the specializations is used. Unions and supporting enumerations are defined irrespective of the existence of associations to use them. One-to-many associations map to a bounded sequence of such values.

9 Service Model Platform Specific Models
9.1 DDS PSM

The DDS Services PSM defines IDL files for each package defined in the Services PIM. For each method on each interface class an IDL struct for a DDS topic named for the method is generated; each parameter is mapped to an attribute of the IDL struct. This is unless there is only one attribute (of IDL struct stereotype) in which case the topic type is defined in the Domain Model (i.e., it corresponds to the parameter’s class). Note that the PIM only defines in parameters, there are no return parameters defined and all methods have at least one parameter.

The DDS PSM maps the request_all_navigation_data and request_navigation_data method to the DDS discovery, publish and subscribe functionality. Consequently these methods are not explicitly defined by the DDS IDL.

9.2 GraphQL PSM

The GraphQL Data Model PSM defines a single combined schema file for the Data Model and Service Model defined by the PIM.

The schema supports GraphQL clients for the interfaces defined for the CMS and Subsystem components in the Service Model PIM. Mutations are used to invoke PIM interface methods; queries and subscriptions are used to process those invocations.

The PSM method for connecting to other components is through the underlying HTTPS web service connection. Web-sockets are used for subscription callbacks.

Specific rules for the MDA code generation from the Service Model PIM to the GraphQL PSM IDL are as follows:

- Each interface method in the Service Model is mapped to a (query) type, an input type and update type based on the method parameters; these are for queries, mutations and subscriptions, respectively.
- To invoke a method a client makes a mutation.
- To process a method a client makes a subscription or query.
- The GraphQL schema Query type supports queries for any combination of interface methods in the Service Model.
- The GraphQL schema Mutation type supports invocation of single or multiple instances of any combination of interface methods in the Service Model.
- The GraphQL schema Subscription type supports subscription for any combination of interface methods in the Service Model.
- The GraphQL PSM maps the request_all_navigation_data and request_navigation_data methods to the GraphQL subscription types.

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Deleted: The GraphQL Services PSM defines a set of schema files for each package defined in the Services PIM. For each method on each interface class a GraphQL GraphQL Query type is generated; each parameter is mapped to an attribute of the Query type.

Deleted: The GraphQL PSM maps the request_all_navigation_data and request_navigation_data methods to the GraphQL subscription types.

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