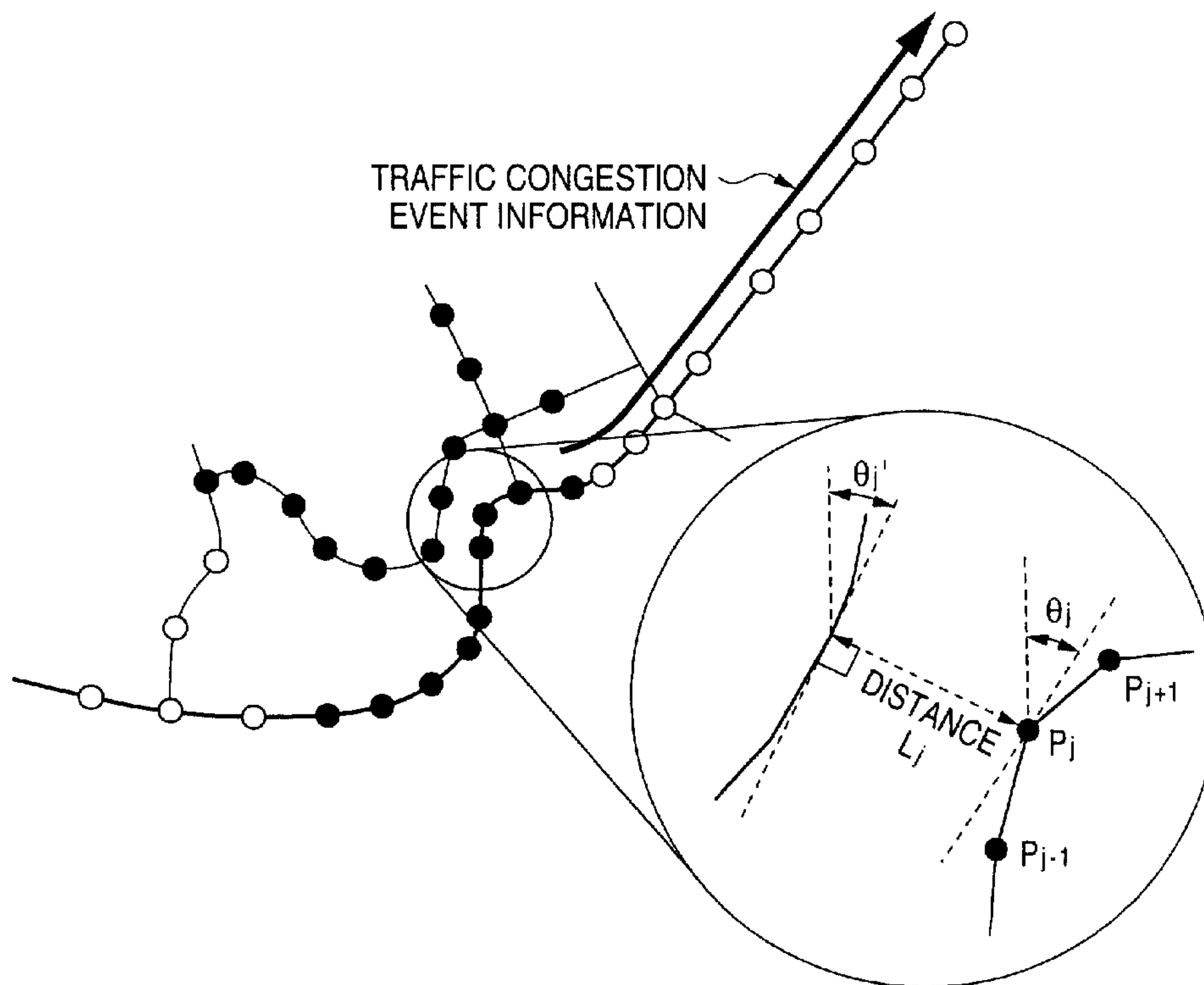




(86) Date de dépôt PCT/PCT Filing Date: 2002/04/25
(87) Date publication PCT/PCT Publication Date: 2002/11/07
(85) Entrée phase nationale/National Entry: 2003/10/02
(86) N° demande PCT/PCT Application No.: JP 2002/004168
(87) N° publication PCT/PCT Publication No.: 2002/088634
(30) Priorité/Priority: 2001/04/27 (2001-132610) JP

(51) Cl.Int.⁷/Int.Cl.⁷ G01C 21/00, G09B 29/10, G08G 1/0969
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(54) Titre : PROCEDE DE TRANSFERT D'INFORMATIONS DE POSITION SUR UNE CARTE NUMERIQUE
(54) Title: METHOD OF TRANSMITTING POSITION INFORMATION OF DIGITAL MAP



(57) Abrégé/Abstract:

A digital map position information transfer method capable of improving the matching accuracy at a reception side. A digital map position information transfer method in which a transmission side transmits a vector shape on a digital map and a reception side identifies the vector shape on its digital map by map-matching. The transmission side selects as an end point of the vector shape a point where a plurality of candidate points will not be easily caused upon map matching and transmits the vector shape having the end point at the selected point to the reception side. This prevents erroneous matching at the reception side and accurately transfers information on the position on the digital map.



ABSTRACT OF THE DISCLOSURE

It is an object of the invention to provide a method of transmitting position information of a digital map which can enhance matching precision on a receiving
5 side.

The invention provides a method of transmitting position information of a digital map in which a transmitting side transmits a vector shape on the digital map and a receiving side specifies the vector shape on a
10 self-digital map by map matching, wherein the transmitting side selects a portion in which a plurality of candidate points are generated with difficulty during the map matching as an endpoint of the vector shape and transmits the vector shape having the endpoint in the portion to the
15 receiving side. Mismatching on the receiving side can be prevented and the position information on the digital map can be transmitted accurately.

DESCRIPTION

Method of Transmitting Position Information of Digital Map

5 <Technical Field>

The present invention relates to a method of transmitting position information of a digital map, and more particularly to a method in which data to be transmitted are devised to accurately transfer a position
10 on a digital map to the receiving side.

<Background Art>

In recent years, a vehicle mounting a navigation onboard machine has rapidly been increased. The navigation
15 onboard machine holds a digital map data base and displays a traffic jam or an accident position on a map based on traffic jam information or accident information which is provided from a traffic information center, and furthermore, executes a path search by adding their information to
20 conditions.

The data base of the digital map is created by several companies in our country, and the map data include an error because of a difference in a basic view and a digitization technique and the error differs depending on a
25 digital map created by each company. For this reason, in

the case in which an accident position is to be transmitted through traffic information, for example, there is a possibility that a position on a different road might be identified as the accident position depending on the type
5 of the digital map data base held in the onboard machine if longitude and latitude data on the position are singly presented.

In order to improve the inaccuracy of the information transmission, conventionally, a node number is
10 defined to a node such as an intersection present in a road system and a link number is defined to a link representing a road between nodes, each intersection and a road are stored corresponding to a node number and a link number in a digital map data base created by each company, a road is
15 specified based on a link number in traffic information, and a point on a road is displayed by an expression method, for example, a distance from a head. However, the node number and the link number which are defined in the road system are to be newly changed according to the new
20 construction or alteration of a road. Moreover, if the node number or the link number is changed, digital map data created by each company are to be updated. For this reason, a method of transmitting the position information of a digital map by using a node number and a link number
25 requires a great social cost for maintenance.

In order to improve such a respect, the inventors

of the invention have proposed the following method in JP-A-11-214068 and JP-A-11-242166.

In this method, when transmitting the position of a road on which an event such as a traffic jam or an accident occurs, the information providing side transmits, to the receiving side, "road shape data" comprising a coordinate string having a node in which the road shape of a road section having a predetermined length including the event position is arranged on the road and an interpolation point (the vertex of a polygonal line approximating the curved line of the road, which will be referred to as a "node" including the interpolation point if there is no notice in this specification) and "event position data" indicative of an event position based on a relative position in the road section represented by the road shape data, and the side receiving these information carries out map matching by using the road shape data, specifies a road section on a self-digital map, and specifies an event generation position in the road section by using the event position data.

Moreover, the inventors of the invention have also proposed a method in which a procedure for the map matching is executed efficiently. This method employs a sequential matching technique, and the receiving side calculates the coordinates of an event position by using the received road shape data and event position data and adds the event

position as a node in the node string of the road shape data. Then, the map matching is executed in order from a node on the start edge of the node string and a point which is most greatly matched with a node indicative of the event
5 position is specified as the event position on the road of a self-digital map.

In the case in which the position information of the digital map is to be transmitted by these methods, there is an important problem in that matching precision on
10 the receiving side is to be enhanced. In the sequential matching method, particularly, when the start point of the map matching is wrong, the error tends to be taken over by the subsequent map matching so that mismatching is apt to be caused. Moreover, there is a problem in that the
15 mismatching is easily generated in an intersection having a small intersecting angle.

The invention solves these problems and has an object to provide a method of transmitting the position information of a digital map which can enhance matching
20 precision on the receiving side.

<Disclosure of the Invention>

The invention provides a method of transmitting position information of a digital map in which a
25 transmitting side transmits a vector shape on the digital map and a receiving side specifies the vector shape on a

self-digital map by map matching, wherein the transmitting side selects a portion in which a plurality of candidate points are generated with difficulty during the map matching as an endpoint of the vector shape and transmits
5 the vector shape having the endpoint in the portion to the receiving side.

Moreover, the transmitting side shifts an endpoint of the vector shape to a portion in which a plurality of candidate points are generated with difficulty during the
10 map matching, and transmits, to the receiving side, the vector shape having an endpoint position deformed.

Furthermore, the transmitting side deforms an azimuth of the vector shape at an intersection in the middle of the vector shape in such a direction as to
15 increase an angle formed by the vector shape and a connecting vector to be connected to the vector shape when the angle is small at the intersection, and transmits, to the receiving side, the vector shape having the azimuth deformed.

20 Consequently, mismatching on the receiving side can be prevented and the position information on the digital map can be transmitted accurately.

<Brief Description of the Drawings>

25 Fig. 1 is a view illustrating a processing on the transmitting side according to a first embodiment,

Fig. 2 is a flow chart showing a processing procedure on the transmitting side in a position information transmitting method according to the first embodiment,

5 Fig. 3 is a view illustrating a processing on the transmitting side according to a second embodiment,

Fig. 4 is a flow chart showing a processing procedure on the transmitting side in a position information transmitting method according to the second
10 embodiment,

Fig. 5 is a view illustrating the deformation of shape vector data in the position information transmitting method according to the second embodiment,

Fig. 6 is a view illustrating a processing on the
15 transmitting side according to a third embodiment,

Fig. 7 is a flow chart showing a processing procedure on the transmitting side in a position information transmitting method according to the third embodiment,

20 Fig. 8 is a block diagram showing the structure of a device for executing the position information transmitting method according to an embodiment,

Figs. 9(a) and 9(b) are diagrams showing data to be transmitted in the position information transmitting method
25 according to the embodiment, and

Fig. 10 is a flow chart showing a map matching

procedure in the position information transmitting method according to the embodiment.

In the drawings, the reference numerals 10 and 20 denote a position information transmitting / receiving
5 device, the reference numerals 11 and 21 denote a position information transmitting portion, the reference numerals 12 and 22 denote a position information receiving portion, the reference numeral 13 denotes a map matching portion, the reference numeral 14 denotes a digital map display portion,
10 the reference numeral 15 denotes a digital map data base, the reference numeral 16 denotes an event information input portion, the reference numeral 17 denotes a position information converting portion, and the reference numeral 18 denotes a shape vector data deforming portion.

15

<Best Mode of Carrying Out the Invention>

In a method of transmitting position information of a digital map according to the invention, the transmitting side selects the node of a start point and deforms the
20 position of the node such that mismatching is not generated on the receiving side.

Fig. 8 shows a position information transmitting / receiving device 10 for exchanging event generation information on a road together with another device 20 as an
25 example of a device for executing the position information transmitting method according to the invention.

The device 10 comprises a position information receiving portion 12 for receiving information including road shape data and event position data from a position information transmitting portion 21 of the device 20, a digital map data base 15 for storing digital map data, a map matching portion 13 for carrying out map matching by using the road shape data and the event position data to specify an event position on a digital map, a digital map display portion 14 for superposing and displaying the event position on the map, an event input portion 16 for inputting generated event information, a position information converting portion 17 for generating road shape data and event position data for transmitting the event information, a shape vector data deforming portion 18 for deforming the road shape data such that the mismatching is not generated on the receiving side, and a position information transmitting portion 11 for transmitting position information including the generated road shape data and event position data to a position information receiving portion 22 of the device 20.

Figs. 9(a) and 9(b) show an example of the position information transmitted from the position information transmitting portion 11, and Fig. 9(a) shows shape vector data string information for specifying a road section which includes the road shape data and Fig. 9(b) shows traffic information including relative distance data from a

reference point provided in the road section to the event position.

The position information converting portion 17 acquires coordinates (longitude / latitude) of nodes p1 to
5 pn in the road section including the event generation position from the digital map data base 15 based on the event information input from the event input portion 16, generates road shape data (a shape vector data string), and furthermore, sets a reference point in the road section
10 represented by the shape vector data string and generates traffic information including relative distance data from the reference point to the event generation position.

The position information converting portion 17 selects the node p1 to be the start point for the map
15 matching on the receiving side such that mismatching is not caused when generating the shape vector data string. This processing will be described in a first embodiment.

(First Embodiment)

Fig. 2 shows a procedure for selecting the node p1
20 by the position information converting portion 17. This procedure is executed in accordance with a program by a computer for implementing the function of the position information converting portion 17 based on the program. With reference to a view of Fig. 1, the procedure will be
25 described.

In Fig. 1, a solid line indicates a road on a

digital map, and a white circle and a black circle indicate a node included in the shape of the road. In the case in which a traffic jam event is generated in a position on the road which is shown in an arrow, a node to be a start point
 5 for map matching on the outside of an event generation section (that is, a node to be the first node p_1 in a shape vector data string) is shown in the black circle. The position information converting portion 17 selects a node in which mismatching is not generated on the receiving side
 10 from the black circle based on the procedure shown in Fig. 2.

Step 1 : Select an object section included in the shape vector data string,

Step 2 : Pick up some nodes positioned in
 15 the vicinity of the outside of an endpoint in the object section,

Step 3 : Give a number (p_1 to p_m) to each node,

Step 4 : In order from a first node p_j with
 20 $j = 1$,

Step 5 : Calculate a distance L_j between p_j and an adjacent road and an intercept azimuth angle difference $\Delta \theta_j$, and

Step 6 : Decide a decision value ε_j of the
 25 node p_j by the following (Equation 1).

$$\varepsilon_j = \alpha \cdot L_j + \beta \cdot |\Delta \theta_j|$$

$$= \alpha \cdot L_j + \beta \cdot |\theta_j - \theta_{j'}| \quad (\text{Equation 1})$$

α and β represent predetermined coefficients.

Step 7, Step 8 : Carry out the processings of the
5 Step 5 and the Step 6 for all the nodes p_1 to p_m ,

Step 9 : Select a node p_r having the
greatest decision value ϵ , and

Step 10 : Select a path from the node p_r to
an endpoint in an original object section through a path
10 search and add the path to the object section.

By the execution of such a processing, a point in
which the receiving side makes an error with difficulty can
be selected as the first node p_1 in the shape vector data
string to be the start point for the map matching.

15 (Second Embodiment)

In a second embodiment, description will be given
to a method of deforming the endpoint position of an object
section to prevent mismatching on the receiving side when a
road running in parallel with an object road in the object
20 section is present.

As shown in Fig. 3, in the case in which an object
road in an object section is present between a parallel
track 1 and a parallel track 2, the shape vector data
deforming portion 18 shifts an endpoint P in the object
25 section to the position of P' , thereby preventing the
endpoint P from being mismatched as a point on the parallel

track 1. If P' is too close to the parallel track 2, there is a possibility that the endpoint P might be mismatched as a point on the parallel track 2. The shape vector data deforming portion 18 selects the position of P' such that
 5 there is not such a possibility.

Fig. 4 shows a processing procedure for the shape vector data deforming portion 18. This procedure is executed in accordance with a program by a computer for implementing the function of the shape vector data
 10 deforming portion 18 based on the program.

Step 11 : Select the object section of an object road by the position information converting portion 17,

Step 12 : Pick up the endpoint node P of the
 15 object section,

Step 13 : Draw a perpendicular on each of peripheral adjacent roads from P and calculate the coordinates of m intersecting points P_j ,

Step 14 : Calculate a decision value ϵ_j of
 20 each P_j from a distance L_j between P and P_j and an intercept azimuth $\Delta \theta_j$ based on the (Equation 1),

Step 15 : Select a node P_r taking a minimum decision value ϵ_r in all ϵ_j ,

Step 16 : Decide whether the node P_r is
 25 present on the left or right side in the direction of progress of a shape vector data string, and

Step 17 : Put P' on a point provided apart by $L' = \{\kappa L_r, L_0\}$ from the endpoint P in the direction of the perpendicular of the object road on the opposite side of the node P_r .

5 Herein, κ represents a predetermined coefficient of $0 < \kappa < 1$ and L_0 represents a predetermined decision value of approximately 120 m. $L' = \kappa L_r$ is obtained if κL_r is equal to or smaller than L_0 , and $L' = L_0$ is obtained if κL_r is greater than L_0 .

10 Next, it is decided whether or not the endpoint is too close to another road by the shift of the endpoint P to P' . If the endpoint is too close to another road, L' is reduced every $1/10$. The processing is repeated until the state of the endpoint is eliminated. More specifically,

15 Step 18 : Set a reduction coefficient $k = 10$,

Step 19 : Carry out the same processing as that of each of the Step 13 and the Step 14 from P' to obtain a distance L'_j between P' and P'_j and an intercept azimuth $\Delta\theta'_j$, and calculate a decision value ϵ'_j of each P'_j to select minimum ϵ' s,

Step 20 : Decide whether or not $\epsilon'_s > \mu \epsilon_r$ is satisfied. μ represents a predetermined value of approximately 1.2 to 2,

At the Step 20, if $\epsilon'_s > \mu \epsilon_r$ is not satisfied,

25 Step 21 : Set the reduction coefficient k to $k = k - 1$,

Step 22 : Reduce L' every $1/10$ based on $L' = (k/10) \cdot L'$ and repeat the procedure from the Step 19.

In the case in which L' is reduced or $\epsilon's > \mu \epsilon r$ is satisfied even if the L' is not reduced,

5 Step 23 : Modify the coordinates of the start point P to P' ,

Step 24 : Connect a point provided apart from P over the object section by a distance L_1 (a predetermined distance) and P' , thereby deforming a shape (a dotted line
10 in Fig. 3),

Step 25 : Set the position error of the node P' to be the position error of transmitted data (Fig. 9(a)).

In this case, P' is shifted so that the shape itself of the object section is deformed and the direction does not
15 always need to be changed as shown in Fig. 5.

By deforming the endpoint of the object section, thus, the mismatching on the receiving side can be prevented.

In the case in which the parallel tracks 1 and 2
20 running in parallel with the object section are present as shown in Fig. 3, there can also be proposed a method for displacing the whole object section in parallel. In this case, it is preferable that all the nodes should be shifted in the same direction by a distance L' between P and P' (a
25 left and right offset distance).

(Third Embodiment)

In a third embodiment, description will be given to a method of deforming a node position in an object section to prevent mismatching on the receiving side in the case in which there is a branch path that an object road in the
5 object section intersects at a small angle.

The entry and exit paths of an interchange intersect a main track at a small angle as shown in Fig. 6.

Therefore, in the case in which sequential matching is carried out by using a shape vector data string
10 representing an object section by the receiving side, mismatching is apt to be caused. The shape vector data deforming portion 18 shifts the position of a node in the object section to P_{j+1}' , thereby preventing the mismatching.

Also in this case, if a point of P_{j+1}' is too close to
15 another connecting road, there is a possibility that the mismatching might be caused. Therefore, the shape vector data deforming portion 18 selects the position of P_{j+1}' such that there is not such a possibility.

Fig. 7 shows the processing procedure of the shape
20 vector data deforming portion 18 in this case. This procedure is executed in accordance with a program by a computer for implementing the function of the shape vector data deforming portion 18 based on the program.

Step 31 : Select the object section of an
25 object road by the position information converting portion 17,

Step 32 : Extract an intersection node in the object section and give a number to each node (p_1 to p_m),

Step 33 : In order from a first node p_j with $j = 1$,

5 Step 34 : Calculate $\Delta \theta_{jk}$ for all connecting roads (intersecting roads) k on a vicinal intersection present in a range of $\pm L_0$ (L_0 represents a predetermined distance of approximately 120 m) around the intersection node p_j . $\Delta \theta_{jk}$ is obtained by $\Delta \theta_{jk} = \theta_j - \theta_{jk}$ when

10 θ_j : a turning angle at the node p_j on the object road, and

θ_{jk} : a turning angle for the object road of the intersecting road k as shown in Fig. 6.

Step 35 : Calculate an evaluation value ε_{jk} for each connecting road by (Equation 2).

$$\varepsilon_{jk} = \alpha |\Delta \theta_{jk}| + \beta \cdot L_{ji} \quad (\text{Equation 2})$$

Herein, L_{ji} represents a distance from the node p_j to an intersection in which the object connecting road k is present.

Step 36 : If all ε_{jk} are equal to or greater than a specified value ε_0 , the processing proceeds to Step 46. If no so, that is, a connecting road to intersect at a small angle is present,

25 Step 37 : Extract $k = r$ with a minimum evaluation value ε .

Subsequently, the shape of the object road is deformed such that the connecting angle of the object road and the connecting road r is increased, and furthermore, a space with an intersection having the connecting road r is increased if the same intersection is shifted longitudinally. Moreover, the evaluation value is obtained after the deformation. If the object road is too close to another connecting road due to the deformation, the amount of deformation is decreased every $1/10$ and the decrease is repeated until such a state is eliminated. More specifically,

Step 38 : $m = 10$ is set,

Step 39 : the connecting angle is increased as follows: when $\Delta \theta_{jr} \neq 0$ is not satisfied, and:

15 $\Delta \theta_{jr}$ is positive, $\theta_{j'} = \theta_{j-m} \cdot \delta \theta$

$\Delta \theta_{jr}$ is negative, $\theta_{j'} = \theta_{j+m} \cdot \delta \theta$

$\delta \theta$ represents a predetermined value of approximately 1.5 degrees.

Step 40 : Increase the intersection space to $L_{ji'} = L_{ji+m} \cdot \delta L$ when $L_{ji} \neq 0$ is satisfied. δL represents a predetermined distance of approximately 10 m.

Step 41 : Calculate an evaluation value $\epsilon_{jk'}$ of each connecting road after the deformation and decide whether or not all $\epsilon_{jk'}$ are greater than $\mu \epsilon_{jr}$ in order to obtain the result of the deformation. When $\epsilon_{jk'}$ are not greater than $\mu \epsilon_{jr}$,

Step 42 : $m = m - 1$ is set and the procedure of the Steps 39 and 40 is repeated,

At the Step 41, in the case in which the amount of deformation is decreased or $\epsilon_{jk'} > \mu \epsilon_{jr}$ is satisfied even
 5 if the same amount is not decreased,

Step 43 : Modify the position of the node p_j by $L_{ji'}$ and set p_{j+1} to a position placed apart by a distance L (a predetermined distance) in a $\theta_{j'}$ direction,

Step 44 : Set p_{j+2} to a place positioned at a
 10 distance $2L$ along the object road,

Step 45 : Calculate the direction errors of the nodes p_j to p_{j+2} and the position errors of the nodes p_{j+1} and p_j and set them to the transmitted data (Fig. 9(a)), and

15 Step 46, Step 47 : Repeat the procedure from the Step 34 for all the intersection nodes p_1 to p_m .

By deforming the object section, thus, it is possible to prevent mismatching on the receiving side.

While the positions of p_{j+1} and p_{j+2} are modified
 20 at the Steps 43 and 44 with the direction deformation of p_j , this processing is not always required. In the case in which the modification of the position is not carried out, the direction error of the node p_j and the position error of the node p are set at the Step 45.

25 At the Step 39, moreover, the direction deformation is not carried out if $\Delta \theta_{jr} \doteq 0$ is satisfied. In the case

of a lattice-shaped road system, there is a possibility that running might be carried out on the outside of the road if the angle is forcedly changed.

Fig. 10 shows a processing procedure to be carried
 5 out by the map matching portion 13 on the receiving side when receiving the position information shown in Fig. 9(a) in which the shape vector data are deformed.

Step 51 : Receive the position information,
 Step 52 : Determine a candidate point for a
 10 map matching start point,
 Step 53 : Carry out map matching,
 Step 54 : Calculate a position error and a direction error between the coordinates of each node in the received shape vector data and the nearest point on the
 15 road section of a digital map which is defined by the map matching, respectively,
 Step 55 : Decide whether or not the position errors and direction errors of all the nodes are proper as compared with error information included in the received
 20 position information. If the errors are proper,
 Step 56 : Decide that the matching is successful and define the road section.

If the errors are not proper in the Step 55,

Step 57 : Retrieve and determine a candidate
 25 point other than the matching starting candidate point in consideration of the position errors and the direction

errors.

By such a processing, it is possible to accurately specify a position on a digital map which is transmitted. When the transmitting side selects the matching start point
5 and deforms the shape vector data as described in each embodiment, the receiving side can prevent the generation of the mismatching even if a sequential matching method or a shape matching method is to be employed.

While the description has been given, as an example,
10 to the case in which the position on the road of the digital map is transmitted, the invention can be applied to the case in which positions on various shape vectors represented on a digital map such as rivers or a contour line in addition to the road are to be transmitted.

15 While the invention has been described in detail with reference to the specific embodiments, it is apparent to the skilled in the art that various changes and modifications can be made without departing from the spirit and scope of the invention.

20 The application is based on Japanese Patent Application (2001 - 132610) filed on April 27, 2001 and the contents thereof are incorporated by reference.

<Industrial Applicability>

25 As is apparent from the above description, in the position information transmitting method according to the

invention, mismatching on the receiving side can be prevented so that matching precision can be enhanced. Accordingly, position information on a digital map can be transmitted accurately.

CLAIMS

1. A method of transmitting position information of a digital map for transmitting a vector shape on the digital map from a transmitting side and specifying the vector shape on a digital map in a receiving side by map matching at the receiving side, the method comprising the steps of:

selecting a portion in which a plurality of candidate points are generated with difficulty during the map matching as an endpoint of the vector shape; and

transmitting the vector shape having the endpoint in the portion to the receiving side,

wherein the steps of the selecting and transmitting are executed at the transmitting side.

2. A method of transmitting position information of a digital map for transmitting a vector shape on the digital map from a transmitting side and specifying the vector shape on a digital map in a receiving side by map matching
5 at the receiving side, the method comprising the steps of:

setting a plurality of candidate points for an endpoint of the vector shape,

drawing a perpendicular on a vicinal vector shape from each of the candidate points,

10 calculating a distance between an intersecting
point and the candidate point and a difference in angle
between an intercept azimuth of the intersecting point and
an intercept azimuth of the candidate point, and

 selecting, for the endpoint of the vector shape, a
15 candidate point determined by a decision value including
the distance and the difference in angle between the
intercept azimuths as elements,

 wherein the steps of setting, drawing, calculating,
and selecting are executed at the receiving side.

3. A method of transmitting position information of a
digital map for transmitting a vector shape on the digital
map from a transmitting side and specifying the vector
shape on a digital map in a receiving side by map matching
5 at the receiving side, the method comprising the steps of:

 shifting an endpoint of the vector shape to a
portion in which a plurality of candidate points are
generated with difficulty during map matching; and

 transmitting the vector shape having an endpoint
10 position deformed to the receiving side,

 wherein the steps of shifting and transmitting are
executed at the transmitting side.

4. A method of transmitting position information of a
digital map for transmitting a vector shape on the digital

map from a transmitting side and specifying the vector
shape on a digital map in a receiving side by map matching
5 at the receiving side, the method comprising the steps of:

drawing a perpendicular on each of vicinal vector
shapes from an endpoint of the vector shape;

calculating a distance between an intersecting
point and the endpoint and a difference in angle between an
10 intercept azimuth of the intersecting point and an
intercept azimuth of the endpoint;

selecting the intersecting point based on a
decision value including the distance and the difference in
angle between the intercept azimuths as elements; and

15 shifting the endpoint in an opposite direction to
the intersecting point from the endpoint,

wherein the steps of drawing, calculating,
selecting, and shifting are executed at the transmitting
side.

5. A method of transmitting position information of a
digital map for transmitting a vector shape on the digital
map from a transmitting side and specifying the vector
shape on a digital map in a receiving side by map matching
5 at the receiving side, the method comprising the steps of:

deforming an azimuth of the vector shape at an
intersection in the middle of the vector shape in such a
direction as to increase an angle formed by the vector

shape and a connecting vector to be connected to the vector
10 shape when the angle is small at the intersection; and

transmitting the vector shape having the azimuth
deformed to the receiving side;

wherein the steps of deforming and transmitting are
executed at the transmitting side.

6. The method of transmitting position information
according to claim 5, further comprising the steps of:

extracting intersection included in the vector
shape,

5 calculating an angle formed by the connecting
vector to be connected to an intersection to be noted and
an intersection provided in the vicinity thereof and the
vector shape and a distance between the intersection to be
noted and the intersection to be connected by the
10 connecting vector,

deciding whether or not the deformation is carried
out based on a decision value including at least the angle
and the distance as elements, and

deforming an azimuth of the vector shape at the
15 intersection to be noted in such a direction as to increase
the angle and deforms a position of the intersection to be
noted in such a direction as to increase the distance when
the deformation is to be carried out,

wherein the steps of extracting, calculating,

20 deciding, and deforming are executed at the transmitting side.

7. The method of transmitting position information according to any of claims 3 to 6, further comprising the step of:

transmitting, to the receiving side, information
5 about a distance error or a direction error which is obtained in the deformation of the vector shape together with the vector shape,

wherein the step of the transmitting is executed at the transmitting side.

8. The method of transmitting position information according to claim 7, further comprising the step of

ascertaining whether or not an error between the vector shape on a digital map in the receiving side
5 specified by map matching and a received vector shape is included in a range of the error transmitted from the transmitting side,

wherein the step of ascertaining is executed at the receiving side.

9. A program of a transmitting device for transmitting a vector shape on a digital map which is specified through map matching by a receiving side,

wherein a computer is caused to execute:

5 a procedure for setting a plurality of candidate points of an endpoint of the vector shape;

 a procedure for drawing a perpendicular on a vicinal vector shape from each of the candidate points, and calculating a distance between an intersecting point and
10 the candidate point and a difference in angle between an intercept azimuth of the intersecting point and an intercept azimuth of the candidate point;

 a procedure for calculating a decision value including at least the distance and the difference in angle
15 between the intercept azimuths as elements;

 a procedure for selecting a candidate point to be an endpoint of the vector shape based on the decision value; and

 a procedure for generating the vector shape
20 including the selected candidate point as an endpoint.

10. A program of a transmitting device for transmitting a vector shape on a digital map which is specified through map matching by a receiving side,

 wherein a computer is caused to execute the
5 procedures of:

 drawing a perpendicular on each of vicinal vector shapes from an endpoint of the vector shape, and calculating a distance between an intersecting point and

the endpoint and a difference in angle between an intercept
10 azimuth of the intersecting point and an intercept azimuth
of the endpoint;

calculating a decision value including at least the
distance and the difference in angle between the intercept
azimuths as elements;

15 selecting the intersecting point based on the
decision value;

shifting the endpoint in an opposite direction to
the intersecting point from the endpoint;

calculating the decision value in such a state that
20 the endpoint is shifted;

correcting a shifting distance of the endpoint
based on the decision value in such a state that the
endpoint is shifted; and

a procedure for generating the vector shape
25 including the shifted endpoint.

11. A program of a transmitting device for transmitting
a vector shape on a digital map which is specified through
map matching by a receiving side,

wherein a computer is caused to execute:

5 a procedure for extracting an intersection included
in the vector shape;

a procedure for calculating an angle formed by a
connecting vector to be connected to an intersection to be

noted and an intersection provided in the vicinity thereof
10 and the vector shape, and a distance between the
intersection to be noted and the intersection connected by
the connecting vector;

a procedure for calculating a decision value
including the angle and the distance as elements;

15 a procedure for extracting the connecting vector
based on the decision value;

a procedure for deforming an azimuth of the vector
shape at the intersection to be noted in such a direction
as to increase an angle formed by the connecting vector
20 thus extracted;

a procedure for calculating the decision value in
such a state that the angle is changed;

a procedure for correcting an amount of change in
the angle based on the decision value in such a state that
25 the angle is changed; and

a procedure for generating the vector shape having
the angle changed.

FIG. 1

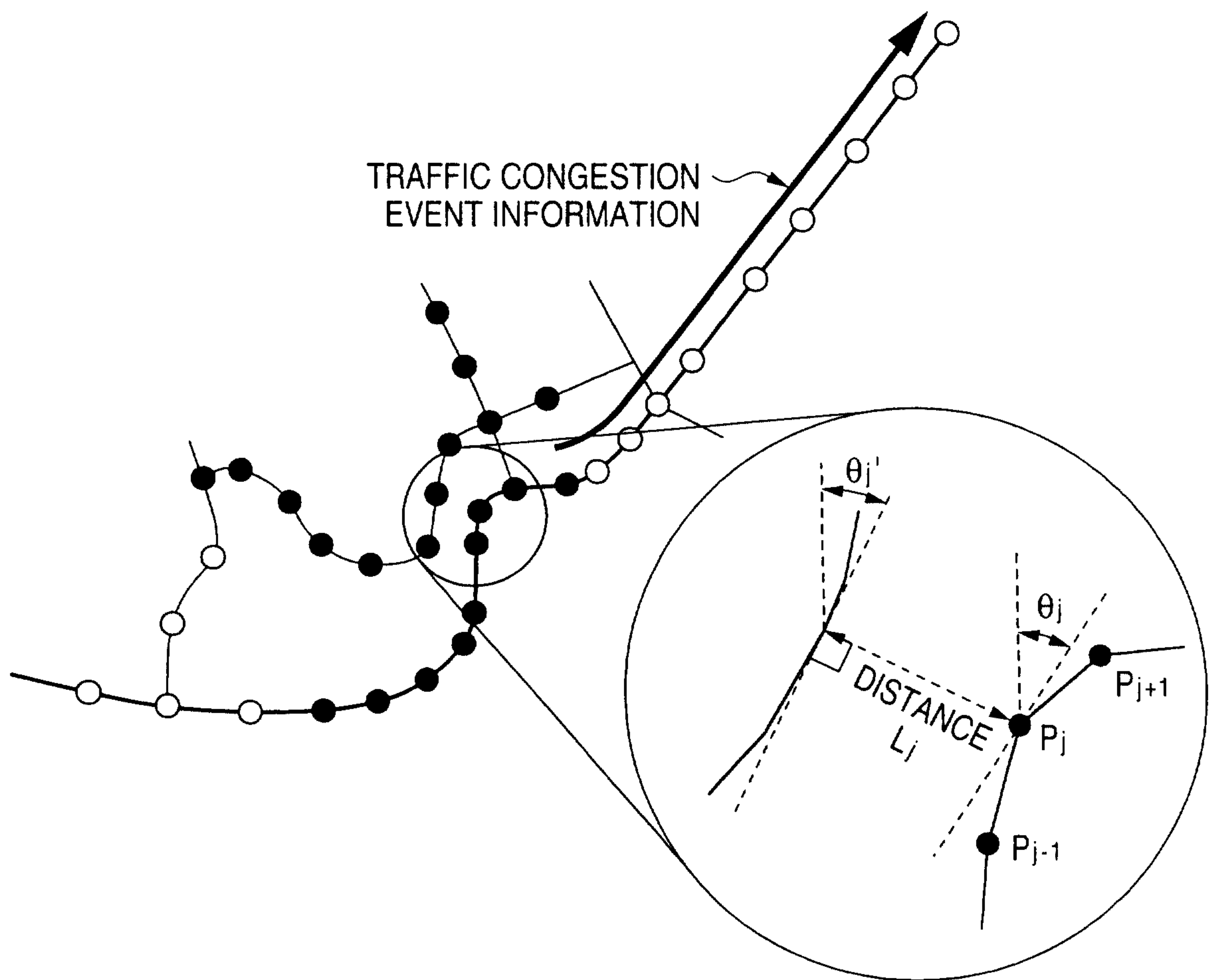


FIG. 2

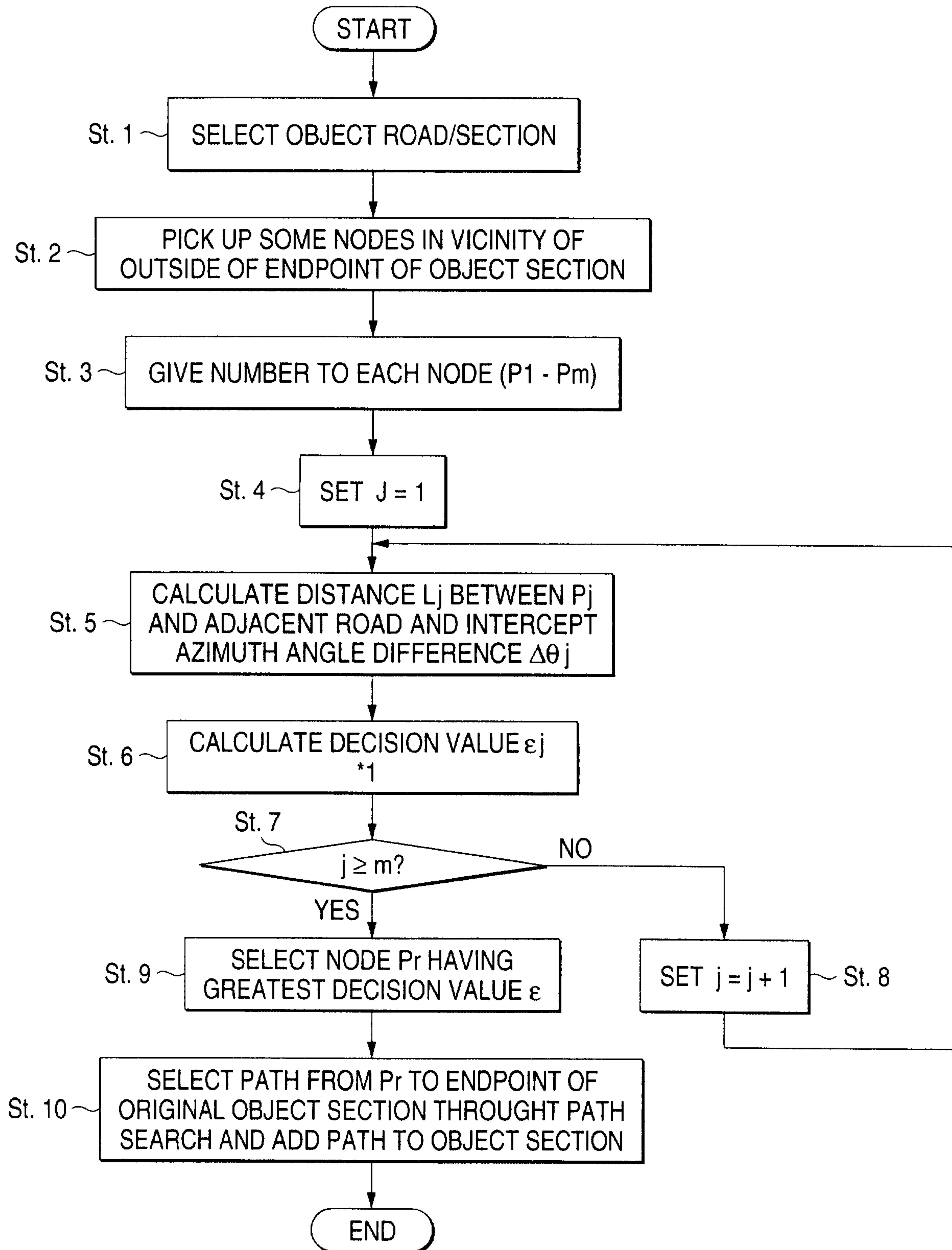


FIG. 3

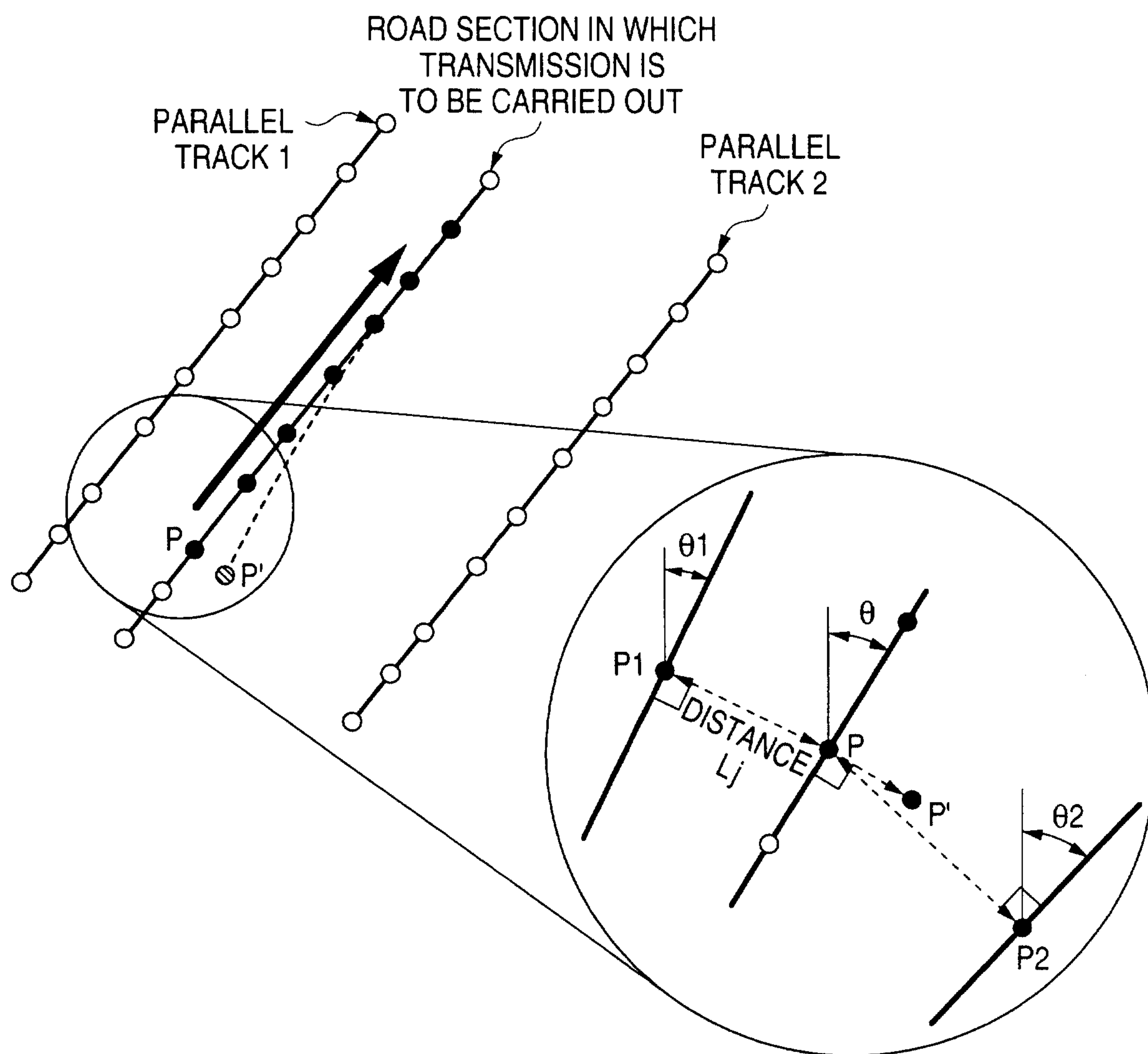


FIG. 4

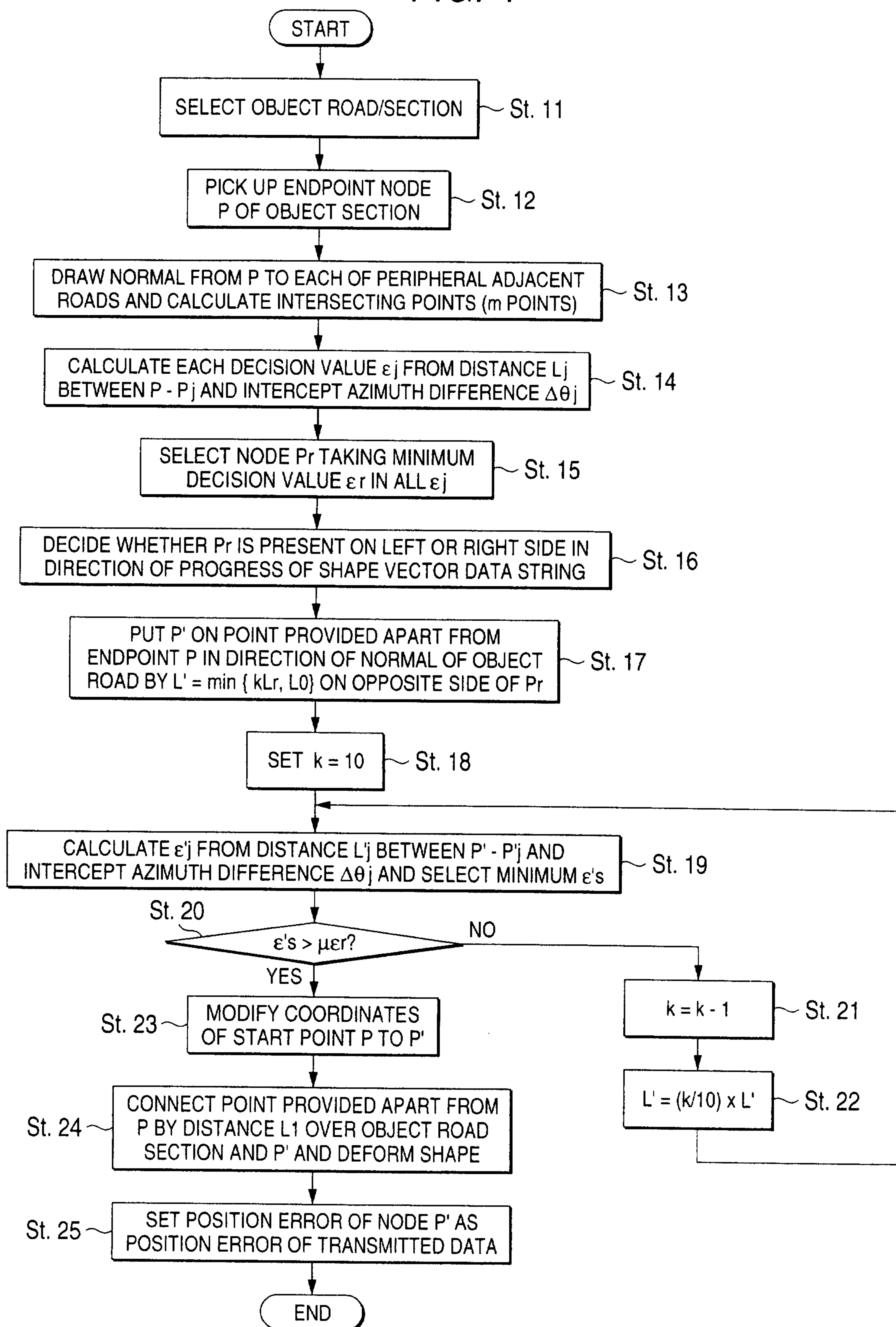


FIG. 5

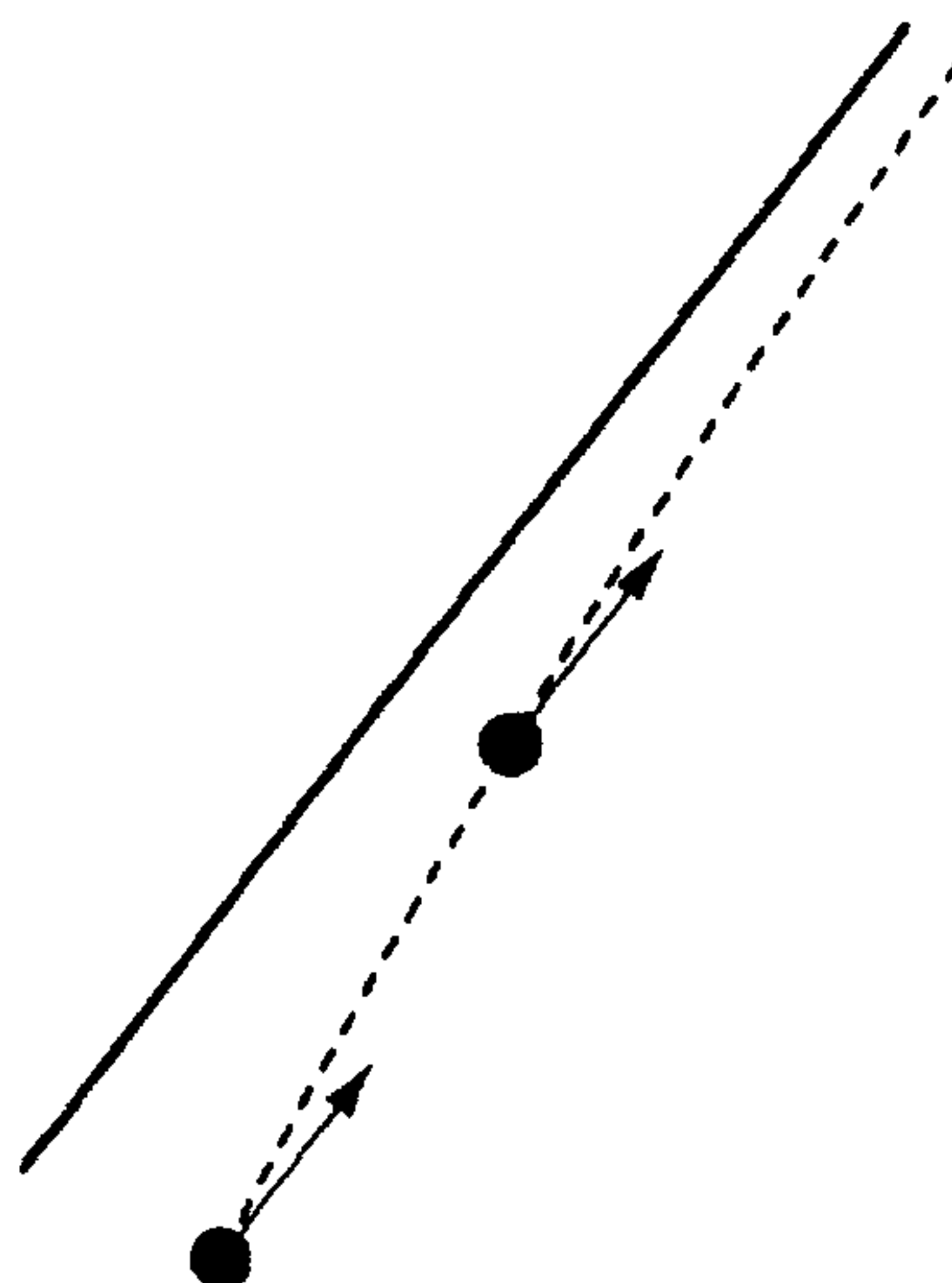


FIG. 6

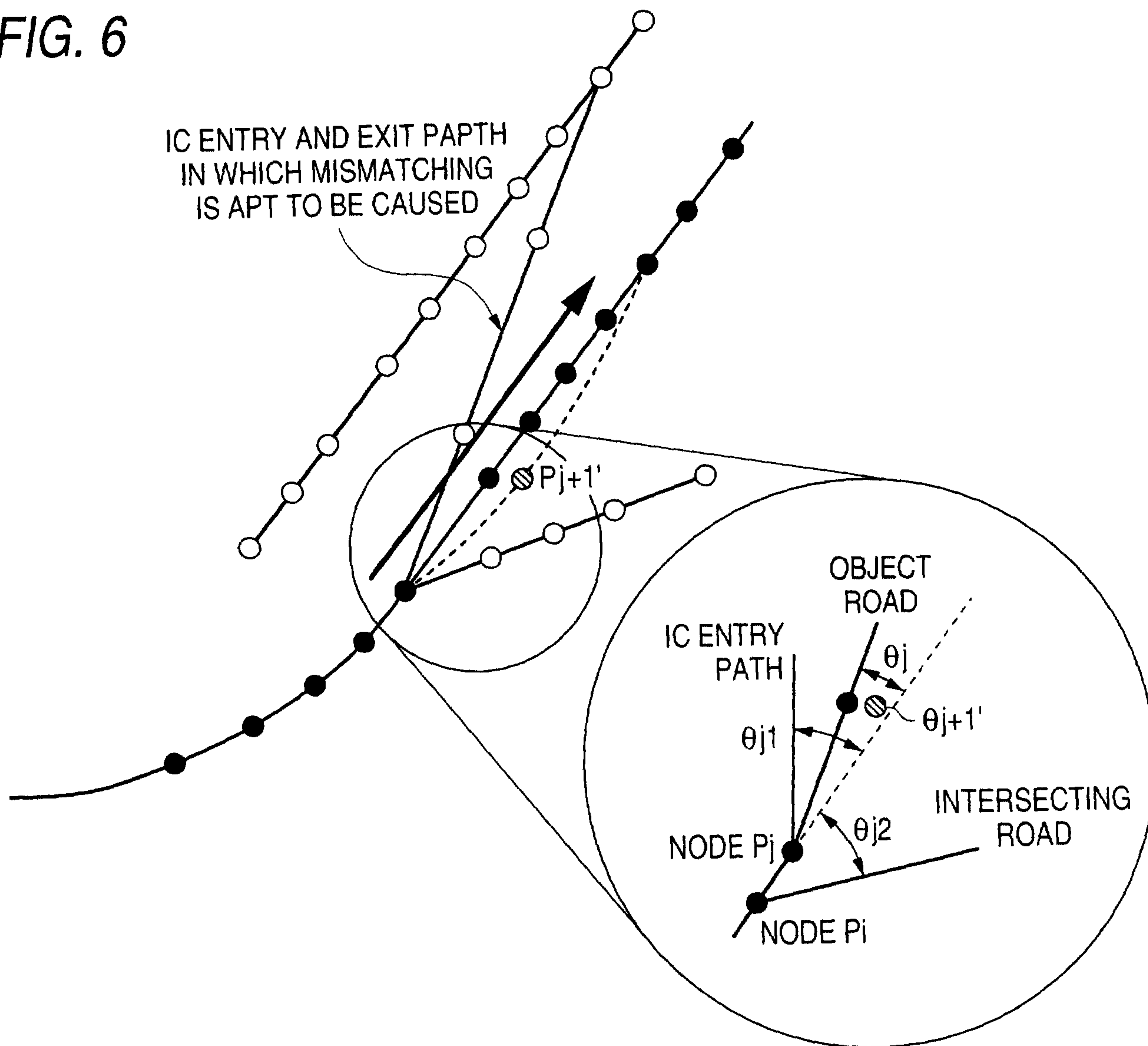


FIG. 7

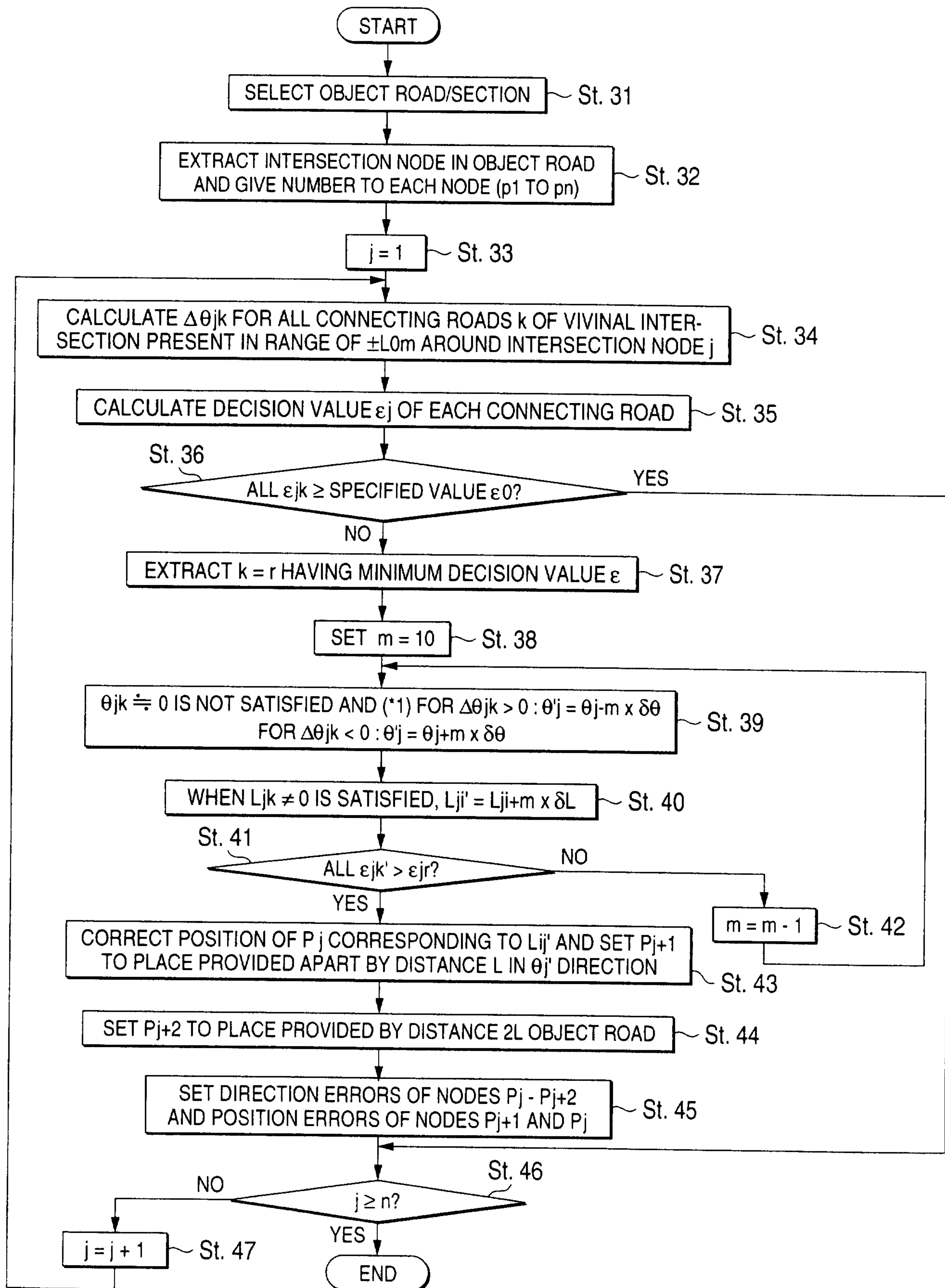


FIG. 8

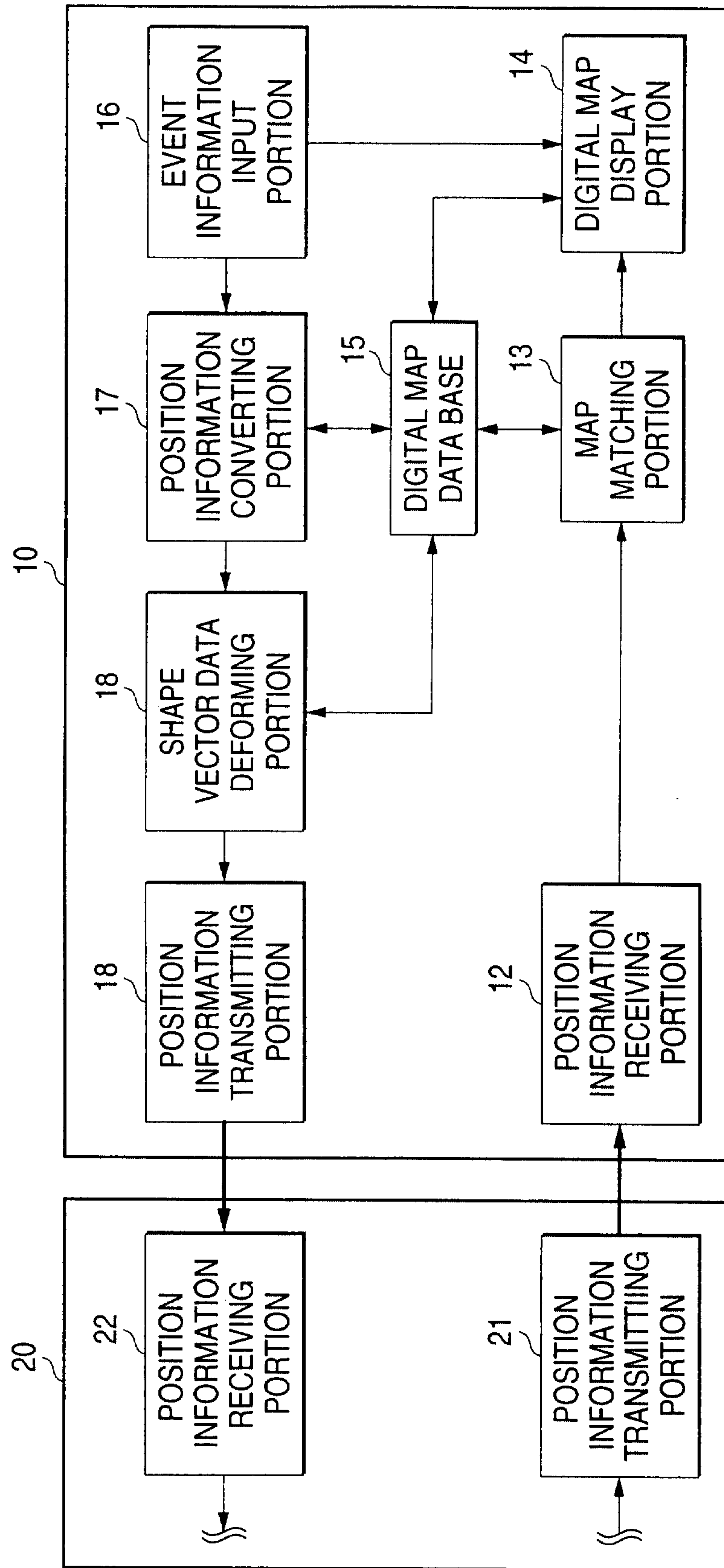


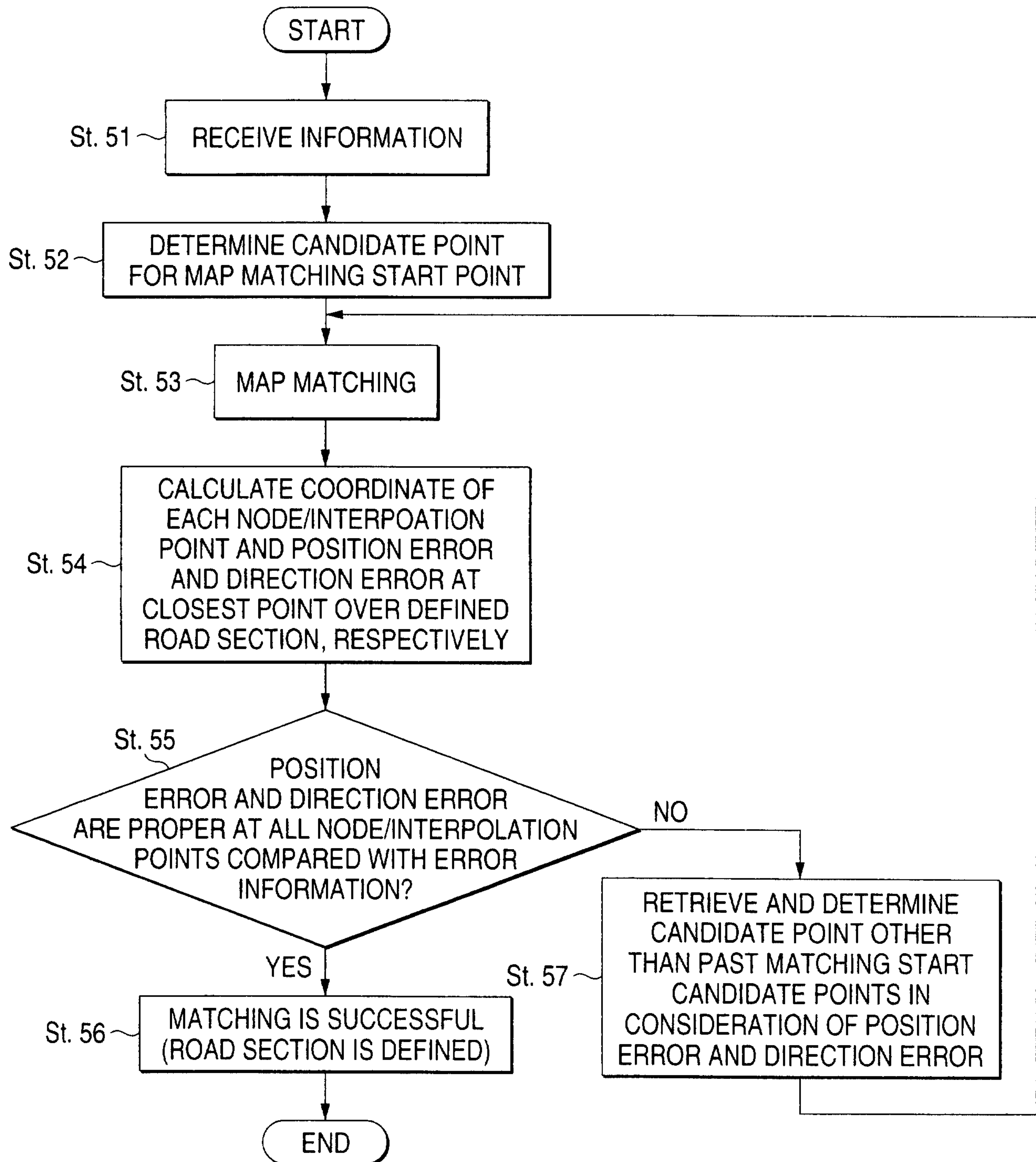
FIG. 9 (a)

VECTOR DATA TYPE (= ROAD)	
PRECISION INFORMATION OF SHAPE ACQUIRING SOURCE MAP DATA	
ONE-WAY DIRECTION (FORWARD/REVERSE/NONE)	
TOTAL NUMBER OF NODES	
NODE NUMBER p1	
NODE p1 ABSOLUTE COORDINATE IN X DIRECTION (LONGITUDE)	
NODE p1 ABSOLUTE COORDINATE IN Y DIRECTION (LATITUDE)	
p1 POSITION ERROR (m)	p1 DIRECTION ERROR (°)
NODE NUMBER p2	
NODE p1 RELATIVE COORDINATE IN X DIRECTION (LONGITUDE)	
NODE p1 RELATIVE COORDINATE IN Y DIRECTION (LATITUDE)	
NODE p2 ABSOLUTE DIRECTION	
p2 POSITION ERROR (m)	p2 DIRECTION ERROR (°)
⋮	
NODE NUMBER pn	
NODE pn RELATIVE COORDINATE IN X DIRECTION (LONGITUDE)	
NODE pn RELATIVE COORDINATE IN Y DIRECTION (LATITUDE)	

FIG. 9 (b)

VECTOR DATA TYPE (= ACCIDENT)
RELATED REGULATING INFORMATION (1 LANE REGULATION)
OCCURRENCE PLACE REFERENCE POINT NODE NUMBER (= p1)
DIRECTION FLAG (= FORWARD DIRECTION WITH RESPECTED TO NODE STRING)
RELATIVE DISTANCE < m > FROM REFERENCE POINT
⋮
EVENT NUMBER (= TRAFFIC CONGESTION)
MEAN SPEED IN TRAFFIC CONGESTION (= 15km)
OCCURRENCE PLACE REFERENCE NODE NUMBER (= pj)
DIRECTION FLAG (= REVERSE DIRECTION WITH RESPECT TO NODE STRING)
REFERENCE DISTANCE FROM REFERENCE POINT (START EDGE SIDE) < m >
REFERENCE DISTANCE FROM REFERENCE POINT (END EDGE SIDE) < m >

FIG. 10



TRAFFIC CONGESTION
EVENT INFORMATION

