

---

# **Adafruit GPS Library Documentation**

***Release 1.0***

**Tony DiCola**

**Nov 19, 2019**



---

## Contents

---

<b>1</b>	<b>Dependencies</b>	<b>3</b>
<b>2</b>	<b>Installing from PyPI</b>	<b>5</b>
<b>3</b>	<b>Usage Example</b>	<b>7</b>
<b>4</b>	<b>About NMEA Data</b>	<b>9</b>
<b>5</b>	<b>Contributing</b>	<b>11</b>
<b>6</b>	<b>Documentation</b>	<b>13</b>
<b>7</b>	<b>Table of Contents</b>	<b>15</b>
7.1	Simple test . . . . .	15
7.2	adafruit_gps . . . . .	17
7.2.1	Implementation Notes . . . . .	17
<b>8</b>	<b>Indices and tables</b>	<b>19</b>
	<b>Python Module Index</b>	<b>21</b>
	<b>Index</b>	<b>23</b>



GPS parsing module. Can parse simple NMEA data sentences from serial GPS modules to read latitude, longitude, and more.



# CHAPTER 1

---

## Dependencies

---

This driver depends on:

- [Adafruit CircuitPython](#)

Please ensure all dependencies are available on the CircuitPython filesystem. This is easily achieved by downloading the [Adafruit library and driver bundle](#).





## CHAPTER 2

---

### Installing from PyPI

---

On supported GNU/Linux systems like the Raspberry Pi, you can install the driver locally [from PyPI](#). To install for current user:

```
pip3 install adafruit-circuitpython-gps
```

To install system-wide (this may be required in some cases):

```
sudo pip3 install adafruit-circuitpython-gps
```

To install in a virtual environment in your current project:

```
mkdir project-name && cd project-name
python3 -m venv .env
source .env/bin/activate
pip3 install adafruit-circuitpython-gps
```



## CHAPTER 3

---

### Usage Example

---

See `examples/gps_simpletest.py` for a demonstration of parsing and printing GPS location.

Important: Feather boards and many other circuitpython boards will round to two decimal places like this:

```
>>> float('1234.5678')
1234.57
```

This isn't ideal for GPS data as this lowers the accuracy from 0.1m to 11m.

This can be fixed by using string formatting when the GPS data is output.

An implementation of this can be found in `examples/gps_simpletest.py`

```
import time
import board
import busio

import adafruit_gps

RX = board.RX
TX = board.TX

uart = busio.UART(TX, RX, baudrate=9600, timeout=30)

gps = adafruit_gps.GPS(uart, debug=False)

gps.send_command(b'PMTK314,0,1,0,1,0,0,0,0,0,0,0,0,0,0,0,0,0')

gps.send_command(b'PMTK220,1000')

last_print = time.monotonic()
while True:

    gps.update()
```

(continues on next page)

(continued from previous page)

```
current = time.monotonic()
if current - last_print >= 1.0:
    last_print = current
    if not gps.has_fix:
        print('Waiting for fix...')
        continue
    print('=' * 40) # Print a separator line.
    print('Latitude: {0:.6f} degrees'.format(gps.latitude))
    print('Longitude: {0:.6f} degrees'.format(gps.longitude))
```

These two lines are the lines that actually solve the issue:

```
print('Latitude: {0:.6f} degrees'.format(gps.latitude))
print('Longitude: {0:.6f} degrees'.format(gps.longitude))
```

Note: Sending multiple PMTK314 packets with `gps.send_command()` will not work unless there is a substantial amount of time in-between each time `gps.send_command()` is called. A `time.sleep()` of 1 second or more should fix this.

## CHAPTER 4

---

### About NMEA Data

---

This GPS module uses the NMEA 0183 protocol.

This data is formatted by the GPS in one of two ways.

The first of these is GGA. GGA has more or less everything you need.

Here's an explanation of GGA:

											11				
1	2	3	4	5	6	7	8	9	10		12	13	14	15	
\$--GGA,hhmmss.ss,llll.ll,a,yyyy.yy,a,x,xx,x.x,x.x,M,x.x,M,x.x,xxxx*hh															

1. Time (UTC)
2. Latitude
3. N or S (North or South)
4. Longitude
5. E or W (East or West)
6. GPS Quality Indicator,
  - 0 - fix not available,
  - 1 - GPS fix,
  - 2 - Differential GPS fix
7. Number of satellites in view, 00 - 12
8. Horizontal Dilution of precision
9. Antenna Altitude above/below mean-sea-level (geoid)
10. Units of antenna altitude, meters
11. Geoidal separation, the difference between the WGS-84 earth ellipsoid and mean-sea-level (geoid), “-” means mean-sea-level below ellipsoid

12. Units of geoidal separation, meters
13. Age of differential GPS data, time in seconds since last SC104 type 1 or 9 update, null field when DGPS is not used
14. Differential reference station ID, 0000-1023
15. Checksum

The second of these is RMC. RMC is Recommended Minimum Navigation Information.

Here's an explanation of RMC:

												12
1	2	3	4	5	6	7	8	9	10	11		
\$--RMC,hhmmss.ss,A,llll.ll,a,yyyy.yy,a,x.x,x.x,xxxx,x.x,a*hh												

1. Time (UTC)
2. Status, V = Navigation receiver warning
3. Latitude
4. N or S
5. Longitude
6. E or W
7. Speed over ground, knots
8. Track made good, degrees true
9. Date, ddmmyy
10. Magnetic Variation, degrees
11. E or W
12. Checksum

[Info about NMEA taken from here.](#)

## CHAPTER 5

---

### Contributing

---

Contributions are welcome! Please read our [Code of Conduct](#) before contributing to help this project stay welcoming.





## CHAPTER 6

---

### Documentation

---

For information on building library documentation, please check out [this guide](#).



---

Table of Contents

---

## 7.1 Simple test

Ensure your device works with this simple test.

Listing 1: examples/gps\_simpletest.py

```
1  # Simple GPS module demonstration.
2  # Will wait for a fix and print a message every second with the current location
3  # and other details.
4  import time
5  import board
6  import busio
7
8  import adafruit_gps
9
10 # Create a serial connection for the GPS connection using default speed and
11 # a slightly higher timeout (GPS modules typically update once a second).
12 # These are the defaults you should use for the GPS FeatherWing.
13 # For other boards set RX = GPS module TX, and TX = GPS module RX pins.
14 uart = busio.UART(board.TX, board.RX, baudrate=9600, timeout=10)
15
16 # for a computer, use the pyserial library for uart access
17 #import serial
18 #uart = serial.Serial("/dev/ttyUSB0", baudrate=9600, timeout=10)
19
20 # If using I2C, we'll create an I2C interface to talk to using default pins
21 #i2c = busio.I2C(board.SCL, board.SDA)
22
23 # Create a GPS module instance.
24 gps = adafruit_gps.GPS(uart, debug=False) # Use UART/pyserial
25 #gps = adafruit_gps.GPS_GtopI2C(i2c, debug=False) # Use I2C interface
26
27 # Initialize the GPS module by changing what data it sends and at what rate.
```

(continues on next page)

(continued from previous page)

```

28 # These are NMEA extensions for PMTK_314_SET_NMEA_OUTPUT and
29 # PMTK_220_SET_NMEA_UPDATERATE but you can send anything from here to adjust
30 # the GPS module behavior:
31 #   https://cdn-shop.adafruit.com/datasheets/PMTK_A11.pdf
32
33 # Turn on the basic GGA and RMC info (what you typically want)
34 gps.send_command(b'PMTK314,0,1,0,1,0,0,0,0,0,0,0,0,0,0,0,0')
35 # Turn on just minimum info (RMC only, location):
36 #gps.send_command(b'PMTK314,0,1,0,0,0,0,0,0,0,0,0,0,0,0,0,0')
37 # Turn off everything:
38 #gps.send_command(b'PMTK314,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0,0')
39 # Turn on everything (not all of it is parsed!)
40 #gps.send_command(b'PMTK314,1,1,1,1,1,1,0,0,0,0,0,0,0,0,0,0')
41
42 # Set update rate to once a second (1hz) which is what you typically want.
43 gps.send_command(b'PMTK220,1000')
44 # Or decrease to once every two seconds by doubling the millisecond value.
45 # Be sure to also increase your UART timeout above!
46 #gps.send_command(b'PMTK220,2000')
47 # You can also speed up the rate, but don't go too fast or else you can lose
48 # data during parsing. This would be twice a second (2hz, 500ms delay):
49 #gps.send_command(b'PMTK220,500')
50
51 # Main loop runs forever printing the location, etc. every second.
52 last_print = time.monotonic()
53 while True:
54     # Make sure to call gps.update() every loop iteration and at least twice
55     # as fast as data comes from the GPS unit (usually every second).
56     # This returns a bool that's true if it parsed new data (you can ignore it
57     # though if you don't care and instead look at the has_fix property).
58     gps.update()
59     # Every second print out current location details if there's a fix.
60     current = time.monotonic()
61     if current - last_print >= 1.0:
62         last_print = current
63         if not gps.has_fix:
64             # Try again if we don't have a fix yet.
65             print('Waiting for fix...')
66             continue
67         # We have a fix! (gps.has_fix is true)
68         # Print out details about the fix like location, date, etc.
69         print('=' * 40) # Print a separator line.
70         print('Fix timestamp: {}/{}/{} {:02}:{:02}:{:02}'.format(
71             gps.timestamp_utc.tm_mon, # Grab parts of the time from the
72             gps.timestamp_utc.tm_mday, # struct_time object that holds
73             gps.timestamp_utc.tm_year, # the fix time. Note you might
74             gps.timestamp_utc.tm_hour, # not get all data like year, day,
75             gps.timestamp_utc.tm_min, # month!
76             gps.timestamp_utc.tm_sec))
77         print('Latitude: {0:.6f} degrees'.format(gps.latitude))
78         print('Longitude: {0:.6f} degrees'.format(gps.longitude))
79         print('Fix quality: {}'.format(gps.fix_quality))
80         # Some attributes beyond latitude, longitude and timestamp are optional
81         # and might not be present. Check if they're None before trying to use!
82         if gps.satellites is not None:
83             print('# satellites: {}'.format(gps.satellites))
84         if gps.altitude_m is not None:

```

(continues on next page)

(continued from previous page)

```

85     print('Altitude: {} meters'.format(gps.altitude_m))
86     if gps.speed_knots is not None:
87         print('Speed: {} knots'.format(gps.speed_knots))
88     if gps.track_angle_deg is not None:
89         print('Track angle: {} degrees'.format(gps.track_angle_deg))
90     if gps.horizontal_dilution is not None:
91         print('Horizontal dilution: {}'.format(gps.horizontal_dilution))
92     if gps.height_geoid is not None:
93         print('Height geo ID: {} meters'.format(gps.height_geoid))

```

## 7.2 adafruit\_gps

GPS parsing module. Can parse simple NMEA data sentences from serial GPS modules to read latitude, longitude, and more.

- Author(s): Tony DiCola

### 7.2.1 Implementation Notes

#### Hardware:

- Adafruit [Ultimate GPS Breakout](#)
- Adafruit [Ultimate GPS FeatherWing](#)

#### Software and Dependencies:

- Adafruit CircuitPython firmware for the ESP8622 and M0-based boards: <https://github.com/adafruit/circuitpython/releases>

**class** `adafruit_gps.GPS(uart, debug=False)`

GPS parsing module. Can parse simple NMEA data sentences from serial GPS modules to read latitude, longitude, and more.

#### **datetime**

Return struct\_time object to feed `rtc.set_time_source()` function

#### **has\_3d\_fix**

Returns true if there is a 3d fix available. use `has_fix` to determine if a 2d fix is available, passing it the same data

#### **has\_fix**

True if a current fix for location information is available.

#### **in\_waiting**

Returns number of bytes available in UART read buffer

#### **nmea\_sentence**

Return `raw_sentence` which is the raw NMEA sentence read from the GPS

#### **read(*num\_bytes*)**

Read up to `num_bytes` of data from the GPS directly, without parsing. Returns a bytearray with up to `num_bytes` or None if nothing was read

#### **readline()**

Returns a newline terminated bytearray, must have timeout set for the underlying UART or this will block forever!

**send\_command** (*command*, *add\_checksum=True*)

Send a command string to the GPS. If *add\_checksum* is *True* (the default) a NMEA checksum will automatically be computed and added. Note you should NOT add the leading \$ and trailing \* to the command as they will automatically be added!

**update** ()

Check for updated data from the GPS module and process it accordingly. Returns *True* if new data was processed, and *False* if nothing new was received.

**write** (*bytestr*)

Write a bytestring data to the GPS directly, without parsing or checksums

**class** `adafruit_gps.GPS_GtopI2C` (*i2c\_bus*, \*, *address=16*, *debug=False*, *timeout=5*)

GTop-compatible I2C GPS parsing module. Can parse simple NMEA data sentences from an I2C-capable GPS module to read latitude, longitude, and more.

**in\_waiting**

Returns number of bytes available in UART read buffer, always 32 since I2C does not have the ability to know how much data is available

**read** (*num\_bytes=1*)

Read up to *num\_bytes* of data from the GPS directly, without parsing. Returns a bytearray with up to *num\_bytes* or *None* if nothing was read

**readline** ()

Returns a newline terminated bytearray, must have *timeout* set for the underlying UART or this will block forever!

**write** (*bytestr*)

Write a bytestring data to the GPS directly, without parsing or checksums

## CHAPTER 8

---

### Indices and tables

---

- `genindex`
- `modindex`
- `search`





### **a**

`adafruit_gps`, [17](#)



## A

`adafruit_gps` (module), 17

## D

`datetime` (*adafruit\_gps.GPS attribute*), 17

## G

`GPS` (class in *adafruit\_gps*), 17

`GPS_GtopI2C` (class in *adafruit\_gps*), 18

## H

`has_3d_fix` (*adafruit\_gps.GPS attribute*), 17

`has_fix` (*adafruit\_gps.GPS attribute*), 17

## I

`in_waiting` (*adafruit\_gps.GPS attribute*), 17

`in_waiting` (*adafruit\_gps.GPS\_GtopI2C attribute*),  
18

## N

`nmea_sentence` (*adafruit\_gps.GPS attribute*), 17

## R

`read()` (*adafruit\_gps.GPS method*), 17

`read()` (*adafruit\_gps.GPS\_GtopI2C method*), 18

`readline()` (*adafruit\_gps.GPS method*), 17

`readline()` (*adafruit\_gps.GPS\_GtopI2C method*), 18

## S

`send_command()` (*adafruit\_gps.GPS method*), 17

## U

`update()` (*adafruit\_gps.GPS method*), 18

## W

`write()` (*adafruit\_gps.GPS method*), 18

`write()` (*adafruit\_gps.GPS\_GtopI2C method*), 18