3GPP TSG-RAN WG2 Meeting #121 R2-23xxxxx

Athens, Greece, 27th of Feb – 3rd of Mar 2023

**Agenda item: 8.8.2**

**Source: Nokia, Nokia Shanghai Bell**

**Title: Report from [Post120][312][UAV] Mobility Control for UAVs (Nokia)**

**WID/SID: NR\_UAV-Core – Rel-18**

**Document for: Discussion and Decision**

# 1 Introduction

This is to discuss the following:

* [Post120][312][UAV] Mobility Control for UAVs (Nokia)

Scope: Discuss aspects related to mobility control, including:

- Height dependent parameter/configuration adjustment or scaling (e.g. TTT, A4 threshold etc). Discuss which parameters/configuration, options, motivation, benefits/drawbacks.

- Event combination – discuss possible event combinations (e.g. height based event and signal strength events) and motivation/benefits

Output: set of agreeable proposals

Deadline: Long - Kick off: Jan 9th, Deadline for company inputs Jan. 20th. Inactive Period January 23 to 27. Comments on rapporteur summary Jan. 30th to February 3rd

In the next section we elaborate on the open issues for Rel-18 UAV mobility control.

# 2 Discussion

## 2.1 Height-dependent Events

Here we consider how to make use of the height/altitude which is estimated by the UAV UE and in the basic approach – used to decide if LTE-like events H1 or H2 shall be triggered. In LTE Rel-15, when the triggering condition for H1 or H2 was met, the UE was supposed to send the measurement report which could contain the RSRP/RSRQ measurements as well as the UE’s location-related information (*LocationInfo* IE) and the height information. It would be good to confirm what is to be reported in NR when event H1 or H2 is triggered.

|  |
| --- |
| **Question 1: In NR Rel-18 when event H1 or event H2 is triggered, what shall be the content of the measurement report? Please choose from the following options:**1. **Only the parameters from *CommonLocationInfo* IE**
2. **Only the RSRP/RSRQ/SINR measurement results**
3. **The content of the report fully configurable by the network (e.g. RSRP results + *CommonLocationInfo* components)**
4. **Other**
 |
| **Company** | **Answer** | **Comments** |
| Huawei, HiSilicon | c | We think the content of the Measurement Report should include the full report so the network can obtain more information to decide on, e.g., handover. This is the same as in LTE. In principle in NR we should do something different from LTE only if there is a good reason to do so. |
| Ericsson | d | The main goal of the H1/H2 measurements is for flying mode / interference detection. As such, the height information is of the highest interest to NW. Therefore, in our view, the height information must always be in the content of H1/H2 triggered measurement report. Whether to include ***CommonLocationInfo*** and/or**RSRP/RSRQ/SINR** should be configurable by the network. The configurability is important for interference control as it controls the size of the report. We are also fine if height is also optional but in our view it should be separate from the rest. |
| Nokia | c | We believe there is no need to restrict the content of the report to only location-related, height or RSRP/RSRQ. When H1/H2 triggers, the NW will have a rough understanding of the height at which the UAV UE is, so *heightUE* reporting is not essential, although we agree with Ericsson – this kind of information needs to be primarily known to the NW. However, there might be also other cases - where the NW is interested in obtaining UE’s location and/or RSRP/RSRQ/SINR measurement results, but that shall stay flexible. Thus, we prefer c). |
| Qualcomm | c/d | The question seems unclear. In our understanding, the main question is whether CommonLocationInfo alone without any RSRP/RSRQ/SINR measurement can be included. We think that should be possible. It is unclear whether option c here includes that possibility. E.g., if the ‘+’ inside e.g. was changed to ‘and/or’, it would be clearer. |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |

Staying still in the topic of H1/H2 events, it shall be discussed if those events can be combined/configured with Ax events (e.g. A3, A4 or A5 events) and the measurement reporting is triggered only if both events are fulfilled simultaneously. Such approach was suggested e.g. in [1] to handle vertical mobility. It would be also a similar principle as was defined for Rel-17 NTN (i.e. time or location based triggering).

|  |
| --- |
| **Question 2: Do you support combining event H1 or H2 with event Ax to ensure the measurement reporting is triggered only if both events are fulfilled simultaneously? Please note, this does not remove the support for ‘standalone’ use of H1 or H2.** |
| **Company** | **Answer** | **Comments** |
| Huawei, HiSilicon | Yes | We think the combination of Hx and Ax can handle the vertical mobility well. Having only the Ax event makes it harder for the network to ensure the handover of the UAV UE to the target cell timely and correctly. For example, because the signal quality may decrease dramatically at the edge of the serving cell in a vertical direction (the distance between the drone and the gNB may not change or change a little when the drone moves vertically), it is hard to handover the drone to the neighboring cell in time just according to the Ax event because the signal quality is strong before the drone crosses the cell’s edge. However, if the drone considers the combination of the Ax and Hx, it can handover to the neighboring cell timely, according to the height and the quality of the cell. More details can be found in R2-2212638. |
| Ericsson | yes | In case there is consensus for the use case on combining Hn and An events, then also Hn and inter-RAT Bn events should be supported.We could discuss also other combinations and see which ones have good use cases. For example, combining location and height might be useful for network to know if UE is approaching a no-fly zone. Or, per network implementation an area where drone UL interference causes issues for BS. In that case network can at least refrain from scheduling UL for the UE.Finally, how the triggering is combined should be discussed. Should the condition combination H and A/B be both fulfilled during TTT, or should UE evaluate the events independently and triggering is similar to NTN CHO. |
| Nokia | Yes | We think such combination could be defined as the NW could expect the UE to send the reports just at certain heights or make the UE not to send the reports at certain other heights. Scenarios described by Huawei are also valid to consider. Of course, this does not exclude the option of having standalone H1 and H2 events, where just the height above the reference level is considered in report triggering.Agree with Ericsson that we should discuss how this combining is done. However, we wanted to first agree in RAN2 that we pursue this kind of combination of events as a part of this WI. We are not sure if combining other events, e.g. location and height is needed as addressing the no-fly zones may not be in the scope of the WI. |
| Qualcomm | Yes | This should be made possible (in addition to standalone H1/H2) |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |

## 2.2 Height-dependent Adjustments

As the UAV UE can fly high above the ground level (up to 300 meters was supported in LTE Rel-15) it can experience largely varying radio conditions. This effect is especially pronounced when the UAV UE is ascending in NLOS conditions, below the rooftops. When the UAV UE flies higher, above the rooftops (in LOS conditions), it can monitor secondary lobes of distant base station’s antennas [2]. This can result in the UE attempting to HO not to the closest available cell. These circumstances have been used in several RAN2 papers to propose height-dependent actions to be taken for UAV UEs. Those include for example: parameter (e.g. TTT) scaling or using different configuration sets, depending on the altitude. Below we would like to ask the companies to express their support for such adaptations and provide additional information how these could be used and implemented.

|  |
| --- |
| **Question 3: Do you support allowing the UAV UE to perform height-dependent parameter scaling? If yes, please provide the details on which parameters can be scaled and in what kind of scenarios.** |
| **Company** | **Answer** | **Comments** |
| Huawei, HiSilicon | Maybe | We think a height-dependent TTT autonomous scaling by the UAV UE could be considered for NR UAVs. Speed-dependent TTT has been specified in LTE. When the speed of UE changes, the TTT will be scaled accordingly to adjust the reporting delay. Similarly, when the UAV UE moves vertically, the drone could adjust the TTT to ensure that it sends Measurement Reports on time, as the communication environment can change dramatically in the vertical direction. If we follow the legacy mechanism, i.e., reconfiguring the TTT when the aerial UE exceeds a certain height, the configured TTT may not be suitable due to the communication delay and the drone’s high mobility. If the TTT is running at the time UE is crossing a threshold that would trigger scaling, it could anyway conclude the ongoing operation and use the different TTT the next time a condition is triggered. Nevertheless, rather than autonomous scaling by the UE (based on some pre-configuration from the network of a scaling factor or similar), it could be more straightforward to use multiple configuration as in the following question, so we prefer the solution mentioned in Q4 instead. |
| Ericsson | yes | In our view, TTT can be scaled with height. This could be simpler option than Q4 |
| Nokia | No/not necessary | If scaling is understood as multiplying the parameter’s value by factor proportional to/directly dependent on the instantaneous height value then we do not see such need. The existence of speed-dependent TTT scaling (in LTE) does not mean that height-dependent TTT (or other parameter) scaling for UAVs is automatically justified. Please note that in the results shown in multiple papers (including Nokia’s TDocs) it is visible the is no consistent trend (e.g. in terms of received signal level versus height) with increasing/decreasing height. Instead, there is a big change of conditions when the UAV crosses the border between NLOS and LOS conditions (usually associated with below/above rooftops). Thus, continuous scaling, depending on the height, may lead to erroneous decisions.  |
| Qualcomm | No | ‘Scaling’ of parameters based on height can have multiple issues without clear gain, as explained by Nokia.  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |

If you do not think height-dependent parameter scaling is beneficial/feasible then another question is whether the UE could be configured with more than a single configuration (e.g. RRM configuration) – each to be used within certain height region.

|  |
| --- |
| **Question 4: Do you support the option where the UE can be configured with more than a single configuration (e.g. RRM configuration) – each to be used within certain height region? Please provide the details which part of the configuration can be subject to such height-dependence and how the switching between the configurations looks like.** |
| **Company** | **Answer** | **Comments** |
| Huawei, HiSilicon | Yes | We think this could be useful and we prefer this solution compared to the UE “autonomous” scaling (see our answer to Q3 above).  |
| Ericsson | No | This may be rather complicated to implement in specs and the complexity of the solution should be evaluated against the benefits before final decision in case there is support enough to start inspecting this option.Another point is that the functionality will need to be discussed, that is the UE action when the switch happens. First option is that UE drops all filters(L3) and TTT and starts over when threshold to apply the second configuration is fulfilled. Hence, UE starts over all the filters and TTT. Now, how to prevent ping pong and/or delayed reporting? |
| Nokia | Yes | We believe this approach is simpler than scaling (Q3) and more justified. As we have shown in section 2.2 of R2-2212268, the A4 threshold (RSRP-based) can vary a lot, especially when the UAV is in NLOS conditions. Thus, at least having two separate sets of conditions for triggering Ax event reporting, each set being height-dependent, is desirable in our opinion. Naturally, the UE would use event H1 or H2 to detect when a new set of parameters (e.g. A4 threshold) is to be applied.When it comes to the concerns raised by Ericsson, defining requirements for transition period is nothing new. Those exist, e.g. for the case of switching between ‘normal’ measurements and relaxed measurements (for reselection) or for the DRX/eDRX case. We also do not think the UE needs to suddenly clear all the measurements it has conducted in the previous height range (e.g. cellsTriggeredList) when the switching occurs.  |
| Qualcomm | Yes | Cleaner approach is to have more than one configuration each to be used within certain height regions (or above/below certain height threshold(s)).One example of such height-dependent configuration is explained in R2-2211305. To reduce the amount of measurements (and therefore measurement reporting) performed by the UE, height threshold(s) for measurement of a subset of beams can be introduced. |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |

|  |
| --- |
|  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |

|  |
| --- |
|  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |
|  |  |  |

# 3 Conclusion

This report has collected inputs on mobility enhancements for UAVs. As a result the following proposals are made:

# References

1. R2-2212638 *Further discussion on UAV measurement enhancements* 3GPP TSG-RAN WG2 Meeting #120 Toulouse, France, November 14-18, 2022
2. J. Stanczak, D. Kozioł, I. Z. Kovács, J. Wigard, M. Wimmer and R. Amorim, "*Enhanced Unmanned Aerial Vehicle Communication Support in LTE-Advanced*," 2018 IEEE Conference on Standards for Communications and Networking (CSCN), 2018, pp. 1-6, doi: 10.1109/CSCN.2018.8581827.
3. RP-223545 *Revised WID: NR Support for UAV (Uncrewed Aerial Vehicles)* 3GPP TSG RAN Meeting #98e Electronic Meeting, Dec 12 - 16, 2022