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OGC Dynamic Features Discussion Paper

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i. Abstract

<Insert Abstract Text here>

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ogcdoc, OGC document, <tags separated by commas>

iii. Preface

NOTE

Insert Preface Text here. Give OGC specific commentary: describe the technical content, reason for document, history of the document and precursors, and plans for future work. > Attention is drawn to the possibility that some of the elements of this document may be the subject of patent rights. The Open Geospatial Consortium shall not be held responsible for identifying any or all such patent rights.

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Chapter 1. Scope

NOTE

Insert Scope text here. Give the subject of the document and the aspects of that scope covered by the document.

Chapter 2. References

The following normative documents contain provisions that, through reference in this text, constitute provisions of this document. For dated references, subsequent amendments to, or revisions of, any of these publications do not apply. For undated references, the latest edition of the normative document referred to applies.

Insert References here. If there are no references, state “There are no normative references”.

References are to follow the Springer LNCS style, with the exception that optional information may be appended to references: DOIs are added after the date and web resource references may include an access date at the end of the reference in parentheses. See examples from Springer and OGC below.

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ISO / TC 211: ISO 19115-1:2014 Geographic information — Metadata — Part 1: Fundamentals (2014)

ISO / TC 211: ISO 19157:2013 Geographic information — Data quality (2013)

ISO / TC 211: ISO 19139:2007 Geographic information — Metadata — XML schema implementation (2007)

ISO / TC 211: ISO 19115-3: Geographic information — Metadata — Part 3: XML schemas (2016)

OGC: OGC 15-097 OGC Geospatial User Feedback Standard. Conceptual Model (2016)

OGC: OGC 12-019, OGC City Geography Markup Language (CityGML) Encoding Standard (2012)

OGC: OGC 14-005r3, OGC IndoorGML (2014)

Chapter 3. Terms and Definitions

This document uses the terms defined in Sub-clause 5.3 of [OGC 06-121r8], which is based on the ISO/IEC Directives, Part 2, Rules for the structure and drafting of International Standards. In particular, the word “shall” (not “must”) is the verb form used to indicate a requirement to be strictly followed to conform to this Best Practice.

For the purposes of this document, the following additional terms and definitions apply.

3.1. term name

text of the definition

Chapter 4. Conventions

This sections provides details and examples for any conventions used in the document. Examples of conventions are symbols, abbreviations, use of XML schema, or special notes regarding how to read the document.

4.1. Identifiers

The normative provisions in this document are denoted by the URI

<http://www.opengis.net/spec/{standard}/{m.n}>

All requirements and conformance tests that appear in this document are denoted by partial URIs which are relative to this base.

Chapter 5. Dynamic Features

Introductory text

5.1. Geometry in 3 Dimensions

Proposition: We already have sufficient standards to define 3-D geometric objects.

5.1.1. CityGML

CityGML defines the geometry of city objects using the geometric primitives and aggregate elements defined in ISO 19107.

Volumetric shapes are defined using the Boundary Representation (B-Rep) approach. B-Rep defines a 3-dimensional surface which serves as the interface between the interior of the volumetric shape and the exterior. This surface is usually defined by a collection of shape elements which together form a closed surface. CityGML also allows a surface to be defined by a point cloud.

Some structures, such as a tunnel or overpass, pose difficulties for this model. The surface can be constructed so that it continues into the interior of the structure. That would make the interior of a tunnel external to the tunnel object. Not always a desirable result. CityGML provides the concept of a "Closure Surface". A Closure Surface is a surface which is a logical part of the object but does not correspond to a physical part of the object. For example, the entrance to a tunnel can have a closure surface. This surface allows you to treat the tunnel as a single three-dimension entity, even though there is a hole in the bounding surface.

https://en.wikipedia.org/wiki/Boundary_representation

Also look at IndoorGML, and Land/Infrastructure. These three OGC standards should use a common geometry.

5.1.2. SPICE

<https://naif.jpl.nasa.gov/naif/toolkit.html>

At first glance SPICE has many similarities to CityGML.

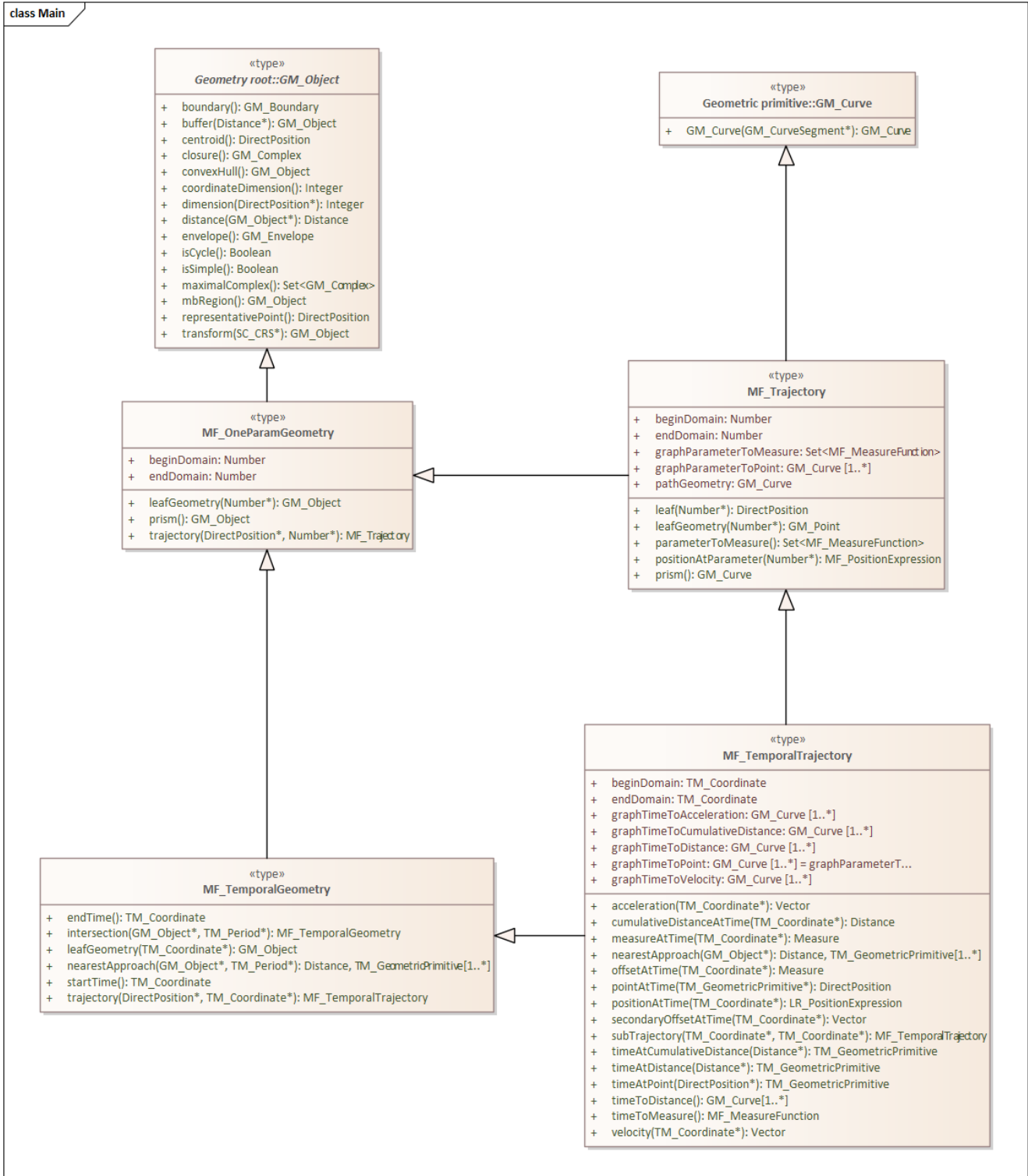
5.2. Temporal Geometry

Proposition: We have sufficient standards to define geometries which change with time.

5.2.1. ISO 19141 - Moving Features

"ISO 19141:2008 defines a method to describe the geometry of a feature that moves as a rigid body."

But a look at 19141 suggests much more than that.



MF_TemporalGeometry

MF_TemporalGeometry is a specialization of MF_OneParamGeometry in which the parameter is time as expressed by TM_Coordinate. TM_Coordinate is specified in ISO 19108; it expresses time as a multiple of a single unit of measure such as year, day, or second.

MF_OneParameterGeometry

A one parameter set of geometries is a function f from an interval $t \in [a, b]$ such that $f(t)$ is a geometry and for each point $P \in f(a)$ there is a one parameter set of points (called the trajectory of P) $P(t) : [a, b] \rightarrow P(t)$ such that $P(t) \in f(t)$. A leaf of a one parameter set of geometries is the geometry $f(t)$

at a particular value of the parameter. The set of geometries forms a prism that is the set of points in the union of the geometries (or the union of the trajectories).

The type "MF_OneParamGeometry" acts as the root classifier for all geometric object classified as one parameter sets of geometric objects. As a one-paramter set, they have "leaf" projections (for each parameter value. As geometric objects they act as the infinite union of all their "leaf" (cross sections for each parameter value).

So if our object it defined by a bounding surface, and that surface is made up of a number of shapes descended from MF_TemporalGeometry, then the surface geometry of our object can change over time. Hence it is not rigid. ISO 19141, when used with CityGML, can also define deforming (plastic) bodies.

5.3. Temporal Properties

Proposition: Features can change in state as well at location

ISO 19141 introduced the concept of a One Parameter Geometry.

MF_OneParamGeometry:

A one parameter set of geometries is a function f from an interval $t \in [a, b]$ such that $f(t)$ is a geometry and for each point $P \in f(a)$ there is a one parameter set of points (called the trajectory of P) $P(t) : [a, b] \ni P(t)$ such that $P(t) \in f(t)$. A leaf of a one parameter set of geometries is the geometry $f(t)$ at a particular value of the parameter. The set of geometries forms a prism that is the set of points in the union of the geometries (or the union of the trajectories).

The type "MF_OneParamGeometry" acts as the root classifier for all geometric object classified as one parameter sets of geometric objects. As a one-paramter set, they have "leaf" projections (for each parameter value. As geometric objects they act as the infinite union of all their "leaf" (cross sections for each parameter value).

According to the Feature Model, geometry is a property of a Feature. Since we have defined MF_OneParamGeometry, it stands to reason that there can be a MF_OneParamProperty. Likewise, there can be a subclass MF_TemporalProperty.

Therefore, MF_TemporalProperty can represent any Feature Property which changes with time. The JSON encoding standard for Moving Features provides us with this capability.

5.3.1. TemporalProperties Object

A TemporalProperties object is a JSON array of ParametricValues objects that groups a collection of dynamic non-spatial attributes and its parametric values with time.

ParametricValues Object

A ParametricValues object is a JSON object that represents a collection of parametric values of dynamic non-spatial attributes that are ascertained at the same times. A parametric value may be a time-varying measure, a sequence of texts, or a sequence of images. Even though the parametric value may depend on the spatiotemporal location, MF-JSON Prism only considers the temporal

dependencies of their changes of value.

5.4. Articulated Geometries

Given a suite of standards which allow you to define time-variant geometric elements, then the next step is to take a collection of those elements and assemble them into a complex object.

An articulated geometry is such an aggregation where each element has less than 6 degrees of freedom. Each element can move, but its movement is constrained by attachment to one or more additional elements.

The aggregate as a whole can also move, but that movement becomes more complex. typically we would model movement of the whole as a trajectory of the center of mass. However, the center of mass of an articulating Feature will change as the relative position of the elements change.

5.4.1. GeoPOSE

The Frame Transform is a representation of the transformation taking an Outer Frame coordinate system to an Inner Frame coordinate system. This abstraction is constrained in GeoPose v 1.0 to only allow transformations involving translation and rotation. The intention is to match the usual concept of a pose as a position and orientation. The formalism that expresses a GeoPose Frame Transform is a pair of Reference Frames, Outer and Inner, each defined by a Frame Specification.

A pose has a valid time (GeoPose_instant)

Discuss outer frame vs Inner Frame

EPSg 4979 is basis for all frames?

insert figure 8

Sequence

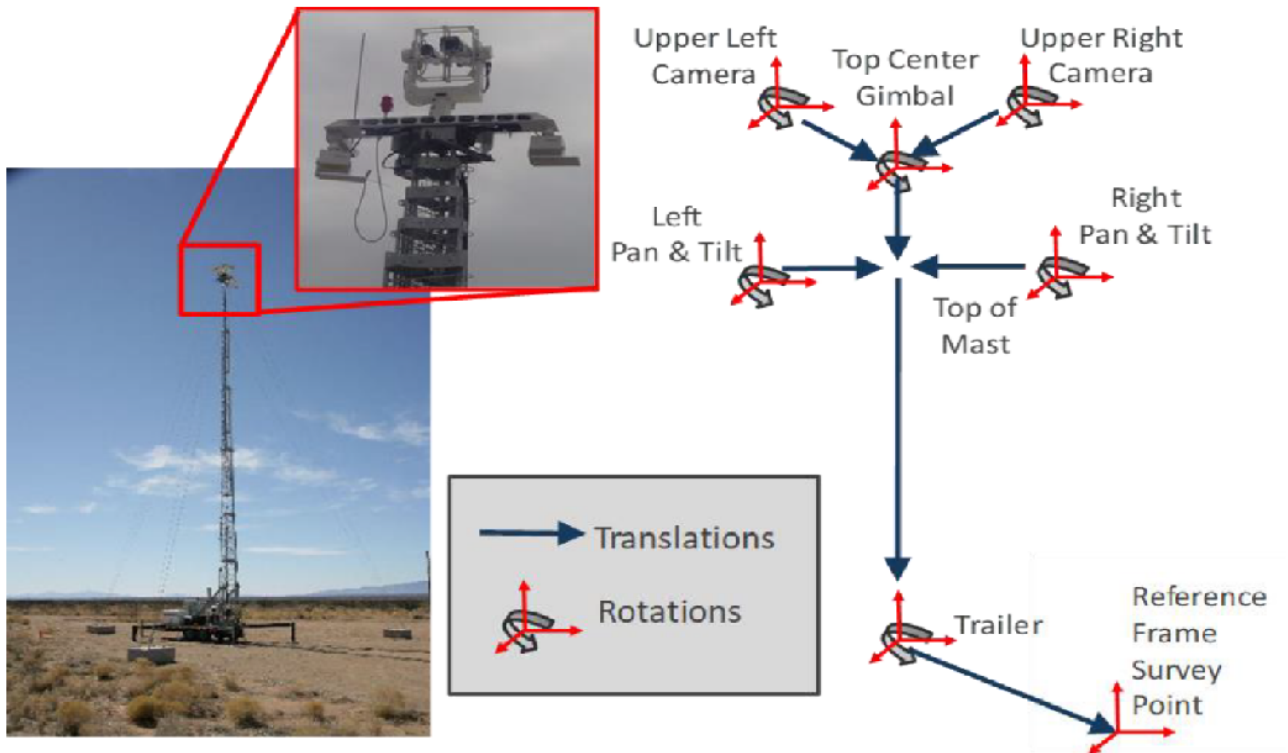
The sequence logical model defines a method for packaging of GeoPose data, where multiple GeoPoses in a sequence share the same Outer Frame and there is a time-dependent changing Inner Frame.

5.4.2. MISB Staging System

MISB 1906 Motion Imagery Metadata (MIMD): Staging System

"The Motion Imagery Metadata (MIMD) Model includes locations, orientations, and kinematics (velocity, acceleration, etc.) of platforms, gimbals, sensors, sensor elements, geospatial and other points. The locations and orientations are either absolute references to a well-known frame of reference (e.g., WGS84) or relative references to other locations and orientations. Each location and orientation pairing define a "stage" that has the potential to be the frame of reference for another location and orientation. Linking stages together forms the Staging System. The Staging System then defines an ability to describe, in metadata, the physical make-up and configuration of a system and the time varying physical relationships of the system and its sub-system components."

The MISB Staging System was designed to capture the instantaneous configuration of an articulated sensor system.



Example Motion Imagery System with Multiple Sensors and Gimbals (Photo credit White Sands Missile Range)

Stage: a single frame of reference located at a point. It defines the location, orientation, and kinematics of a coordinate system located at that point. These properties can be defined in terms of absolute values, or as relative values measured from an "parent" reference system.

Constellation: A system of one or more stages where the parent-child relationships between the stages is sufficient to calculate the absolute values for every stage.

Root Stage: This is the starting point for a Constellation. This stage is expressed in absolute values.

Table 1. Stage System Example

Stage	Component	Parent	Values
1	Reference Frame Survey Point	0	Absolute Position/Orientation
2	Trailer	1	Relative Position / Orientation
3	Left Camera	2	Relative Position / Orientation
4	Right Camera	2	Relative Position / Orientation
5	Top Center Gimbal	2	Relative Position / Orientation
6	Left Upper Camera	5	Relative Position / Orientation
7	Right Upper Camera	5	Relative Position / Orientation

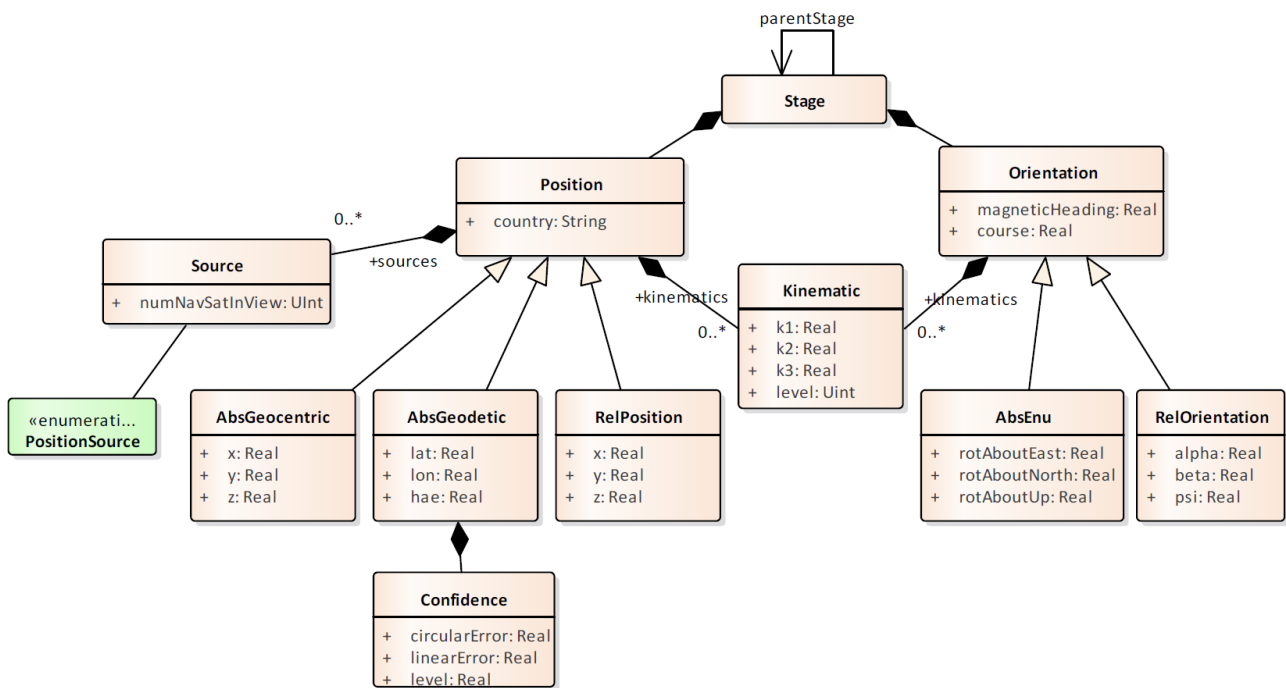
The Staging System's absolute positions use either WGS84 Ellipsoid angular coordinates (i.e., geodetic Latitude, Longitude, Height above Ellipsoid (HAE)), or WGS84 geocentric Earth-Centered

Earth-Fixed (ECEF) Cartesian coordinates (i.e., X, Y, Z).

The Staging System's relative positions use Cartesian coordinates (i.e., x, y, z) measured in meters from the parent stage frame of reference.

The Staging System's orientations use Euler rotations, measured in radians, around three axes (X, Y, and Z) of a righthanded coordinate system. The Staging System's absolute orientation has the X, Y, and Z axes aligned with the East, North, and Up (ENU) respectively.

The Staging System standardizes rotations to use a specific order of rotations. The Staging System uses Tait-Bryan angles with a Primary Rotation Order of Z-Y-X (see Appendix C); thereby the first rotation is around the Z-axis, the second rotation is around the new Y-axis (after rotation around the Z-axis), the final rotation is around the new X-axis (after rotation around the Z and then Y axes).



The Staging system does not explicitly address temporality. However, this information is passed in the MISB KLV metadata stream. As such, each update is associated with the precision time stamp of that packet. In addition, an update can be associated with a Timer as described in section ----

5.4.3. Discussion

Quaternions vs. Euler rotations

Temporal representation

Standardize on a right-handed Cartesian coordinate system for all stages/Poses?

Common concepts:

1. An "anchor" node which ties the relative coordinates to an absolute CRS
2. Local coordinate systems associated with each other through standardized transformations

5.4.4. Lorentz Transformation

A transformation between two different coordinate frames that move at a constant velocity and are relative to each other.

ONLY related to changes in inertial reference frames:

- Inertial frames - motion with a constant velocity
- Non-inertial frames - rotational motion with constant angular velocity, acceleration in curved paths.

In the reference frame "F" which is stationary, the coordinate defined are x, y, z , and t . In another reference frame F' which moves at a velocity v which is relative to F and the observer defines coordinate in the moving reference frame as x', y', z', t' . In both the reference frames the coordinate axis are parallel and they remain mutually perpendicular. The relative motion is along the xx' axes. At $t = t' = 0$, the origins in both reference frames are the same $(x, y, z) = (x', y', z') = (0, 0, 0)$.

The Lorentz factor $\gamma = 1 / (\sqrt{1 - (v^2 / c^2)})$

$$x' = \gamma(x - vt) \quad t' = \gamma(t - vx/c^2) \quad y' = y \quad z' = z$$

This is not a complete coordinate transformation since F' has to be rotated and translated so as to be co-linear with F . However, it does add the impact that relative velocity (v) has on the measurements of x and t . In most cases this impact is negligible (v^2 / c^2 approaches 0). However, when v is a significant percentage of c it should be applied.

5.4.5. Minkowski Space Time

It is basically a combination of 3-dimensional Euclidean Space and time into a 4-dimensional manifold, where the interval of spacetime that exists between any two events is not dependent on the inertial frame of reference.

Minkowski spacetime is a 4-dimensional coordinate system in which the axes are given by (x, y, z, ct)

Where ct is time (t) times the speed of light (c)

$ds^2 = -c^2 dt^2 + dx^2 + dy^2 + dz^2$ = the differential arc length in space time where:

1. dt = change in time
2. dx = change in x direction
3. dy = change in y direction
4. dz = change in z direction

Key point - while a Lorentz transformation deals with spatial measurements, Minkowski space includes time as part of that space-time. Thus ds is an arc length through space-time as opposed to a difference in x as in the Lorentz transform.

Question, since $c^2 dt^2$ is a negative term, does that imply that ct is an imaginary number orthogonal to

x, y, and z (cti) such that $i^2 = -1$?

Yes for complex Minkowski space time. Here it is expressed as $x^2 + y^2 + z^2 + (ict)^2 = \text{const.}$

Complex Minkowski spacetime was replaced with real Minkowski space time where time is a real coordinate rather than an imaginary one.

Where v is velocity, and $x, y, \text{ and } z$ are Cartesian coordinates in 3-dimensional space, and c is the constant representing the universal speed limit, and t is time, the four-dimensional vector $v = (ct, x, y, z) = (ct, \mathbf{r})$ is classified according to the sign of $(c^2 t^2) - r^2$. A vector is **timelike** if $(c^2 t^2) > r^2$, **spacelike** if $(c^2 t^2) < r^2$, and **null** or **lightlike** if $(c^2 t^2) = r^2$. This can be expressed in terms of the sign of $\eta(v, v)$ as well, which depends on the signature. The classification of any vector will be the same in all frames of reference that are related by a Lorentz transformation (but not by a general Poincaré transformation because the origin may then be displaced) because of the invariance of the interval.

5.5. Complex Articulated Systems

This may be a redundant section.

5.6. Mass Properties

This may be a redundant section.

5.7. The Problem of Time

Proposition: Time is in the eye of the beholder. So all measurements of time must be local.

Dynamic Features are not tied to an Earth-centered static existence. Yet the concepts of time used in the geospatial community are almost exclusively based on Earth-centric astronomical phenomena. They also assume a rather coarse degree of granularity. For dynamic features we need to use local clocks with precision down to the nanosecond. We are less concerned with absolute time than with relative time. State B was achieved 37 nanoseconds after State A.

It's only when we begin aggregating these dynamic elements that we begin to worry about "absolute" time. Even then, we are more likely to convert from one local clock to another then to convert to an absolute time.

So if all time is local, we need a Temporal Reference System concept which captures the parameters needed to transform across TRS. A temporal equivalent to GeoPOSE.

Introduce the Timer concept from MISB.

GM_Object

Operation	Parameters	Returns
boundary		GM_Boundary
buffer	Distance	GM_Object

centroid		DirectPosition
closure		GM_Complex
convexHull		GM_Object
coordinateDimension		Integer
dimension	DirectPosition	Integer
distance	GM_Object	Distance
envelope		GM_Envelope
isCycle		Boolean
isSimple		Boolean
maximalComplex		set<GM_Complex>
mbRegion		GM_Object
representativePoint		DirectPosition
transform	SC_CRS	GM_Object

MF_OneParamGeometry

Operation	Parameters	Returns
leafGeometry	Number	GM_Object
prism		GM_Object
trajectory	DirectPosition, Number	MF_Trajectory

MF_TemporalGeometry

Operation	Parameters	Returns
endTime		TM_Coordinate
intersection	GM_Object, TM_Period	TM_TemporalGeometry
leafGeometry	TM_Coordinate	GM_Object
nearestApproach	GM_Object, TM_Period	Distance, TM_GeometricPrimitive
startTime		TM_Coordinate
trajectory	DirectPosition, TM_Coordinate	MF_TemporalTrajectory

MF_Trajectory

Operation	Parameters	Returns
leaf	Number	DirectPosition
leafGeometry	Number	GM_Point
parameterToMeasure		set<MF_MeasureFunction>

positionAtParameter	Number	MF_PositionExpression
prism		GM_Curve

MF_TemporalTrajectory

Operation	Parameters	Returns
acceleration	TM_Coordinate	Vector
cumulativeDistanceAtTime	TM_Coordinate	Distance
measureAtTime	TM_Coordinate	Measure
nearestApproach	GM_Object	Distance, TM_GeometricPrimitive
offsetAtTime	TM_Coordinate	Measure
pointAtTime	TM_GeometricPrimitive	DirectPosition
positionAtTime	TM_Coordinate	LR_PositionExpression
secondaryOffsetAtTime	TM_Coordinate	Vector
subTrajectory	TM_Coordinate, TM_Coordinate	MF_TemporalTrajectory
timeAtCumulativeDistance	Distance	TM_GeometricPrimitive
timeAtDistance	Distance	TM_GeometricPrimitive
timeAtPoint	DirectPosition	TM_GeometricPrimitive
timeToDistance		GM_Curve
timeToMeasure		MF_MeasureFunction
velocity	TM_Coordinate	Vector

MF_PrismGeometry

Operation	Parameters	Returns
geometryAtTime	TM_Coordinate	GM_Object
localCoordinateSystem		SC_CRS
rotationAtTime	TM_Coordinate	MF_RotationMatrix

5.8. Temporal Reference Systems

May be redundant

5.9. Dynamic Features at Relativistic Velocities

At very high velocities, measurements between moving features suffer from relativistic effects. The proposition is to build on Minkowski SpaceTime to address these cases.

More to come.

Annex A: Revision History

Date	Release	Editor	Primary clauses modified	Description
2016-04-28	0.1	G. Editor	all	initial version

Annex B: Bibliography

Example Bibliography (Delete this note).

The TC has approved Springer LNCS as the official document citation type.

Springer LNCS is widely used in technical and computer science journals and other publications

NOTE

- For citations in the text please use square brackets and consecutive numbers:
[1], [2], [3]

– Actual References:

[n] Journal: Author Surname, A.: Title. Publication Title. Volume number, Issue number, Pages Used (Year Published)

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[1] OGC: OGC Testbed 12 Annex B: Architecture. (2015).