

# **Open Geospatial Consortium**

Submission Date: <yyyy-mm-dd>

Approval Date: <yyyy-mm-dd>

Publication Date: <2021-11-01>

External identifier of this OGC® document: <http://www.opengis.net/doc/EG/{standard}/{m.n}>

Internal reference number of this OGC® document: YY-nnnrx

Version: 0.4

Category: OGC® Engineering Guidance

Editor: C. Perey, J. Morley, J. Lieberman, M. Salazar, C. Smyth

## **OGC GeoPose Reviewers Guide**

### **Copyright notice**

Copyright © 2021 Open Geospatial Consortium

To obtain additional rights of use, visit <http://www.opengeospatial.org/legal/>

### **Warning**

This document provides guidance for reviewers of the OGC GeoPose Standard. This document is a non-normative resource and not an official position of the OGC membership. It is subject to change without notice and may not be referred to as an OGC Standard. In addition to this guide, developers, implementers and reviewers may wish to study the OGC GeoPose Users Guide. The guidance provided in this document is not to be referenced as required or mandatory technology in procurements.

Document type: OGC®Engineering Guidance

Document subtype:

Document stage: Draft

Document language: English

## License Agreement

Permission is hereby granted by the Open Geospatial Consortium, ("Licensor"), free of charge and subject to the terms set forth below, to any person obtaining a copy of this Intellectual Property and any associated documentation, to deal in the Intellectual Property without restriction (except as set forth below), including without limitation the rights to implement, use, copy, modify, merge, publish, distribute, and/or sublicense copies of the Intellectual Property, and to permit persons to whom the Intellectual Property is furnished to do so, provided that all copyright notices on the intellectual property are retained intact and that each person to whom the Intellectual Property is furnished agrees to the terms of this Agreement.

If you modify the Intellectual Property, all copies of the modified Intellectual Property must include, in addition to the above copyright notice, a notice that the Intellectual Property includes modifications that have not been approved or adopted by LICENSOR.

THIS LICENSE IS A COPYRIGHT LICENSE ONLY, AND DOES NOT CONVEY ANY RIGHTS UNDER ANY PATENTS THAT MAY BE IN FORCE ANYWHERE IN THE WORLD.

THE INTELLECTUAL PROPERTY IS PROVIDED "AS IS", WITHOUT WARRANTY OF ANY KIND, EXPRESS OR IMPLIED, INCLUDING BUT NOT LIMITED TO THE WARRANTIES OF MERCHANTABILITY, FITNESS FOR A PARTICULAR PURPOSE, AND NONINFRINGEMENT OF THIRD PARTY RIGHTS. THE COPYRIGHT HOLDER OR HOLDERS INCLUDED IN THIS NOTICE DO NOT WARRANT THAT THE FUNCTIONS CONTAINED IN THE INTELLECTUAL PROPERTY WILL MEET YOUR REQUIREMENTS OR THAT THE OPERATION OF THE INTELLECTUAL PROPERTY WILL BE UNINTERRUPTED OR ERROR FREE. ANY USE OF THE INTELLECTUAL PROPERTY SHALL BE MADE ENTIRELY AT THE USER'S OWN RISK. IN NO EVENT SHALL THE COPYRIGHT HOLDER OR ANY CONTRIBUTOR OF INTELLECTUAL PROPERTY RIGHTS TO THE INTELLECTUAL PROPERTY BE LIABLE FOR ANY CLAIM, OR ANY DIRECT, SPECIAL, INDIRECT OR CONSEQUENTIAL DAMAGES, OR ANY DAMAGES WHATSOEVER RESULTING FROM ANY ALLEGED INFRINGEMENT OR ANY LOSS OF USE, DATA OR PROFITS, WHETHER IN AN ACTION OF CONTRACT, NEGLIGENCE OR UNDER ANY OTHER LEGAL THEORY, ARISING OUT OF OR IN CONNECTION WITH THE IMPLEMENTATION, USE, COMMERCIALIZATION OR PERFORMANCE OF THIS INTELLECTUAL PROPERTY.

This license is effective until terminated. You may terminate it at any time by destroying the Intellectual Property together with all copies in any form. The license will also terminate if you fail to comply with any term or condition of this Agreement. Except as provided in the following sentence, no such termination of this license shall require the termination of any third party end-user sublicense to the Intellectual Property which is in force as of the date of notice of such termination. In addition, should the Intellectual Property, or the operation of the Intellectual Property, infringe, or in LICENSOR's sole opinion be likely to infringe, any patent, copyright, trademark or other right of a third party, you agree that LICENSOR, in its sole discretion, may terminate this license without any compensation or liability to you, your licensees or any other party. You agree upon termination of any kind to destroy or cause to be destroyed the Intellectual Property together with all copies in any form, whether held by you or by any third party.

Except as contained in this notice, the name of LICENSOR or of any other holder of a copyright in all or part of the Intellectual Property shall not be used in advertising or otherwise to promote the sale, use or other dealings in this Intellectual Property without prior written authorization of LICENSOR or such copyright holder. LICENSOR is and shall at all times be the sole entity that may authorize you or any third party to use certification marks, trademarks or other special designations to indicate compliance with any LICENSOR standards or specifications. This Agreement is governed by the laws of the Commonwealth of Massachusetts. The application to this Agreement of the United Nations Convention on Contracts for the International Sale of Goods is hereby expressly excluded. In the event any provision of this Agreement shall be deemed unenforceable, void or invalid, such provision shall be modified so as to make it valid and enforceable, and as so modified the entire Agreement shall remain in full force and effect. No decision, action or inaction by LICENSOR shall be construed to be a waiver of any rights or remedies available to it.

# Table of Contents

1. Introduction .....	5
1.1. What is GeoPose? .....	5
1.2. Why is Another Standard Needed? .....	5
1.3. How Does OGC GeoPose Address Diverse Requirements? .....	5
1.4. How Did we Define the OGC GeoPose v 1.0 Scope? .....	5
1.5. Who Will Use the OGC Reviewers Guide? .....	6
1.6. How To Use This Resource .....	6
2. Reviewers Guide Scope .....	7
2.1. References .....	7
2.2. Terms and Definitions .....	7
2.3. GeoPose Glossary .....	9
Conceptual Overview .....	10
3. Key Concepts .....	11
4. Orientation Systems .....	16
5. Positioning Systems .....	19
6. Time-related Concepts .....	23
7. The GeoPose Standard .....	27
7.1. Conceptual Model .....	27
7.2. Logical Model .....	27
7.3. Encodings for Implementation .....	27
8. OGC GeoPose in Context .....	30
8.1. OGC GeoPose connects objects to their representation .....	30
8.2. OGC GeoPose in the Landscape of Standards .....	31
8.3. Standards which Could Reference GeoPose in Normative Clauses .....	32
8.3.1. OGC Standards .....	32
8.3.2. Other SDOs .....	33
8.3.3. Space Science .....	35
8.4. Software that Use or Generate Geospatially-anchored Position and Orientation .....	35
Annex A: Revision History .....	55
Annex B: Bibliography .....	56

## **i. Abstract**

The GeoPose Reviewers Guide is a public resource structured to provide quick answers to questions which a reviewer may have about the [OGC GeoPose specification](#). It is provided to support professionals who need to understand OGC GeoPose and/or are reviewing the GeoPose draft standard but do not wish to implement it.

[GeoPose 1.0](#) is an OGC Implementation Standard for exchanging the position and orientation of real or virtual geometric objects (Poses) within reference frames anchored to the earth's surface (Geo) or within other astronomical coordinate systems. The standard specifies two Basic forms with no configuration options for common use cases, an Advanced form with more flexibility for more complex applications, and five composite GeoPose structures that support time series plus chain and graph structures.

## **ii. Keywords**

The following are keywords to be used by search engines and document catalogues.

GeoPose, ogcdoc, OGC document, OGC Implementation Standard, Geospatially-anchored position and orientation, pose, reviewers

## **iii. Preface**

This version of the GeoPose Reviewers Guide is limited in scope to the draft implementation specification for GeoPose 1.0. Content of this document will be updated when relevant information and feedback to the OGC GeoPose 1.0 SWG is provided and the standard finalized. The Open Geospatial Consortium shall not be held responsible for the accuracy or completeness of this reviewers guide.

Recipients of this document are requested to submit, with their comments, notification of any relevant patent claims or other intellectual property rights of which they may be aware that might be infringed by any implementation of the standard set forth in this document, and to provide supporting documentation.

## **iv. Submitting organizations**

The OGC GeoPose Standards Working Group submitted this document for publication by the Open Geospatial Consortium (OGC).

## **v. Submitters**

The OGC GeoPose Standards Working Group submitted this document for publication by the Open Geospatial Consortium (OGC).

# Chapter 1. Introduction

## 1.1. What is GeoPose?

There are two answers to this question: a conceptual answer and an answer that explains what the standard provides. Conceptual Answer: When a real or digital object's pose is defined relative to a geographical frame of reference it will be called a [make sure that there's 100% alignment between this text and the glossary. Link to the glossary definition?]"geographically-anchored pose." All physical world objects inherently have a geographically-anchored pose. Digital objects may be associated with a geographically-anchored pose (for example, in a real-world overlay or on a stage).

What the Standard Provides: The OGC GeoPose standard defines a conceptual model, a logical model and encodings for the position and orientation of a real or a digital object in a machine-readable form in real world coordinates, a geographically-anchored pose.

## 1.2. Why is Another Standard Needed?

A new standard is required to facilitate the seamless interchange of position and orientation information between proprietary systems and any systems that implement to existing standards. The [review of standards related to GeoPose](#) demonstrates that there are many relevant specifications that could use GeoPose, however, do not provide the elements.

## 1.3. How Does OGC GeoPose Address Diverse Requirements?

The draft [OGC GeoPose 1.0 standard](#) defines data structures for the interoperable exchange of the position and orientation of real or virtual geometric objects (Poses) within reference frames anchored to the earth's surface (Geo). In developing this standard, the SWG sought to use a single conceptual model to address requirements ranging from common use case that benefit from low complexity, and low optionality ("without optional parameters"), to those complex use cases needing high flexibility.

In order to meet the wide range of requirements, the OGC GeoPose specifies:

1. Two basic forms with no configuration options for common use cases,
2. An advanced form with more flexibility for more complex applications, and
3. Five composite structures to support time series plus chain and graph structures.

GeoPose 1.0 is the derived [OGC Implementation Standard](#) for exchanging GeoPoses.

## 1.4. How Did we Define the OGC GeoPose v 1.0 Scope?

While the earth is the focus of the GeoPose 1.0, the specification could also be used in conjunction with other astronomical bodies than the earth.

In the course of developing GeoPose v1.0 and in order to focus on the key objectives of the standard, it was decided to that the following considerations would be out of scope for the v1.0:

- details of any frame transformations (e.g., the radius of the Earth),
- differential properties (i.e., acceleration and velocity) and other physical properties of objects that could be associated with a GeoPose,
- concepts of uncertainty (accuracy and precision),
- camera models or view frustums,
- scaling and other non-rigid transforms,
- interpolation methods in case of complex targets, and
- [FILL IN ANYTHING ELSE WE CAN THINK OF]

**NOTE**

we could divide up and present this scope differently. We could also say that any of the above could be presented in parallel with GeoPose. Many of the aspects which were excluded could be introduced in parallel as more properties in a schema.

## 1.5. Who Will Use the OGC Reviewers Guide?

The GeoPose Reviewers Guide is a resource for those who seek to understand the key concepts used in OGC GeoPose, the requirements it meets and the data structures it specifies.

We intend this guide to be useful for reviewers of the standard as well as decision makers seeking to understand the relevance of this standard in their use cases.

## 1.6. How To Use This Resource

The GeoPose Reviewers Guide is not intended to be read from start to finish. Rather, it is a resource structured to provide quick answers to questions which a reviewer may have about the [OGC GeoPose specification](#). It is provided to support professionals who need to understand OGC GeoPose and/or are reviewing the GeoPose draft standard but do not wish to implement it.

In addition, this guide can provide insights to professionals considering adopting GeoPose for their projects and products.

The GeoPose Reviewers Guide contains hyperlinks which can be used to navigate directly to relevant sections of the guide as well as to sections of the [draft GeoPose specification](#) and the [GeoPose User Guide](#).

# Chapter 2. Reviewers Guide Scope

The GeoPose Reviewers Guide introduces the the **key concepts used in GeoPose** to its **target audiences**.

To identify broadly applicable requirements for GeoPose, the SWG solicited use cases and chose five that were agreed to be representative in nature. To understand the ways in which GeoPose can be used and how it meets requirements identified, this guide can be used in conjunction with the OGC GeoPose [use cases](#) section of the standard.

The choices of [https://data.ogc.org/geopose-swg/pdf/geopose\\_standard.pdf#standardization\\_targets](https://data.ogc.org/geopose-swg/pdf/geopose_standard.pdf#standardization_targets) [standardization targets] made in the GeoPose SWG during standard development are explained in [this section](#) of the present guide.

Finally, this guide explains how GeoPose fits in the landscape of geospatial computing. It compares GeoPose with approaches that have been [taken in other standards](#), and in [open source projects and libraries, and commercial products](#) for encoding geospatially-anchored position and orientation with six degrees of freedom.

## 2.1. References

### TO BE UPDATED WHEN WE HAVE ALL DONE

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

- IETF: RFC 2045 & 2046, Multipurpose Internet Mail Extensions (MIME). (November 1996),
- IETF: RFC 3986, Uniform Resource Identifier (URI): Generic Syntax. (January 2005)
- INSPIRE: D2.8.III.2 Data Specification on Buildings – Technical Guidelines. European Commission Joint Research Centre.
- ISO: ISO 19101-1:2014, Geographic information - Reference model - Part 1: Fundamentals

**NOTE** Each reference has an anchor. That allows users to jump to this citation from any hyperlinked reference in the text. The second part of the anchor is the text that will be displayed such as [RFC 2045](#)

## 2.2. Terms and Definitions

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

For GeoPose, specifically, there is a visual glossary of frequently used terms. To consult the visual GeoPose glossary, visit the GeoPose wiki.

**NOTE**

Which of these boilerplate terms/definitions do we want to keep in the GeoPose Reviewer's Guide?

What is a reviewers guide? What is a users guide? What is a standard?

**2D data**

geometry of features is represented in a two-dimensional space

NOTE In other words, the geometry of 2D data is given using (X,Y) coordinates.

[INSPIRE D2.8.III.2, definition 1]

**2.5D data**

geometry of features is represented in a three-dimensional space with the constraint that, for each (X,Y) position, there is only one Z

[INSPIRE D2.8.III.2, definition 2]

**3D data**

Geometry of features is represented in a three-dimensional space.

NOTE In other words, the geometry of 2D data is given using (X,Y,Z) coordinates without any constraints.

[INSPIRE D2.8.III.2, definition 3]

**application schema**

A set of [conceptual schema](#) for data required by one or more applications. An application schema contains selected parts of the base schemas presented in the ORM Information Viewpoint. Designers of application schemas may extend or restrict the types defined in the base schemas to define appropriate types for an application domain. Application schemas are information models for a specific information community.

OGC Definitions Register at <http://www.opengis.net/def/glossary/term/ApplicationSchema>

**codelist**

A value domain including a code for each permissible value.

**conceptual model**

model that defines concepts of a universe of discourse

[ISO 19101-1:2014, 4.1.5]

**conceptual schema**

1. formal description of a [conceptual model](#)

[ISO 19101-1:2014, 4.1.6]

2. base schema. Formal description of the model of any geospatial information. [Application schemas](#) are built from conceptual schemas.

OGC Definitions Register at <http://www.opengis.net/def/glossary/term/ConceptualSchema>

**Implementation Specification**

Specified on the OGC Document Types Register at <http://www.opengis.net/def/doc-type/is>

**NOTE**

Notice that each definition has an anchor. Anchor text would also be a good idea which we may include latter. Terms used within a definition should be cross-linked to their definition if it is included in this document (see [Application Schema](#) for an example).

## 2.3. GeoPose Glossary

# Conceptual Overview

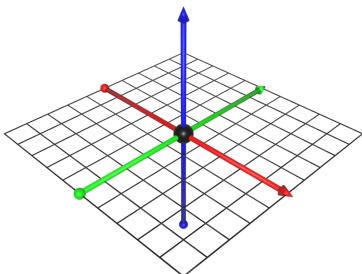
This overview was originally created to facilitate the communication between GeoPose SWG members to reach a shared understanding of concepts related to GeoPose. It has been integrated into this guide to provide readers with a better understanding of the conceptual foundations on which the standard is based.

The definition of each term is accompanied by a visual representation of the concept, a more general explanation and examples of how it may be applied. Additionally, the text includes hyperlinks to connect the different concepts to one another and to illustrate how they are used in other standards and real world applications.

# Chapter 3. Key Concepts

The following list of terms covers the conceptual underpinnings for the GeoPose standard while offering examples of how they are actually employed in different scientific fields and industry sectors.

## (Reference) Frame



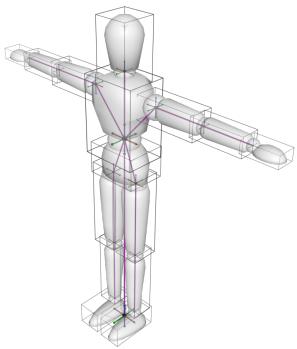
[Frame.blend](#)

As defined in [ISO 19111](#), a reference Frame is a parameter or set of parameters that realize the position of the origin, the scale, and the orientation of a coordinate system.

Another, more practical definition [from Wikipedia](#) is: *"In physics, a (reference) frame consists of an abstract coordinate system and the set of physical reference points that uniquely fix (locate and orient) the coordinate system and standardize measurements within that frame."*

A Reference Frame can be visualized as a subspace with its own [coordinate system](#) (represented with an arrow for each axis and a 2D grid to facilitate measurements) and a point of origin (represented as a sphere at the point where the arrows intersect). Generally, to simplify calculations, the associated coordinate systems are Cartesian in nature, but in the case of [non-euclidean spaces](#), they require more advanced definitions (like the [geographical coordinate systems](#) used in global positioning systems).

## Pose



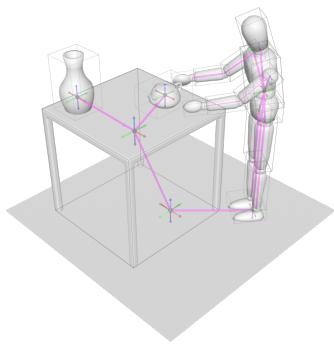
Pose.blend

"A Pose determines the position and orientation of an object (or group of objects) relative to a coordinate system."

In Robotics and Human-Computer Interaction, this concept is often referred to as [Six Degrees of Freedom \(6DoF\)](#) and it is used to specify the position and orientation of an object with great precision (generally, by combining a **Local Positioning System** for the translation and an **Aircraft Principal Axes Orientation System** for the rotation). In this way, it is possible to define complex [kinematic systems](#) that allow the creation of advanced [robotic arms](#) and [exoskeletons](#).

From the point of view of computer graphics, however, a Pose can be seen as a simplified version of a "Transform class" (without the **Scale**-related fields/properties). This direct correspondence implies that a Pose is associated to a single node of an Scene Graph (i.e., the "hand" has a Pose, the "arm" has another Pose, etc.), but, when 3D artists and engineers talk about "Poses", they are generally referring to the combined Pose data of all the components of an entity (i.e., the Pose of a dummy, as seen in the illustration). In fact, most 3D editing software solutions include a separate "Pose mode" so that artists can independently work on the geometry of the different 3D models and on their animation.

## Pose Chain



SceneGraph.blend

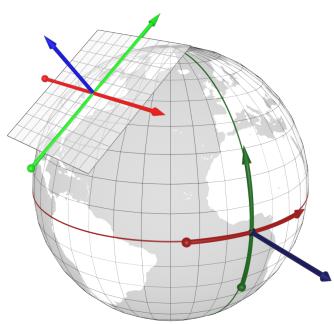
**"A Pose Chain is a sequence of Poses that is used to determine the position and orientation of objects across multiple Frames."**

When dealing with multiple reference [Frames](#) (specially, when they are of different types), it is necessary to perform several complex transformation operations to convert between the different [Coordinate Reference Systems](#). To facilitate this time-consuming process and ensuring that the operations are applied in the right order, the different poses are often organized into one-dimensional sequences of [Poses](#) called "Chains".

In many applications, where a large number of entities have similar Pose Chains, it is common to reorganize this structure into a Graph, so that it is possible to more effectively apply the transformation operations (by storing the result of the repeated operations). In Computer Graphics, this concept is the basis of the "Scene Graph", in which the Transform class instances of the different entities are connected together using a hierarchical graph through (single) parent-children relationships. In this way, the Pose of each entity of the graph is calculated in a [depth-first](#) manner that minimizes the number of required calculations.

NOTE: The definition of GeoPose needs to say that "a GeoPose" is something that complies with the specification but a "geographically-anchored pose" is a concept which can be encoded in proprietary manners or in manner compliant with the standard

## OGC GeoPose



## GeoPose.blend

"A **GeoPose** is a **Pose** in relation to a real-world object (by default, Earth), typically, via a **Geographical Reference Frame**."

The goal of the standardization of GeoPose is to establish a single mechanism to encode the position and orientation of an real/virtual objects within a geographical (ellipsoidal) **Frame**, greatly simplifying the determination of the pose of entities relative to an astronomical object and, consequently, relative to each other.

In practical terms, a GeoPose facilitates the application of a transformation operations to properly position and orientate nodes in a **Scene Graph** (generally, the root one) on a realistic 3D map and/or in an Augmented/Mixed Reality environment.

## Location

"Not to be confused with the term Position, a location is a distinctive region of a space."

While a Position merely specifies a single point within a space (relative to a [Frame](#)), a Location defines a limited region within a space (often with its very own [Frame](#)). A location generally receives a unique name within a context (or within another location) to easily identify it among others and, if necessary, it can also have additional semantic information to further differentiate it (e.g., "Washington D.C.", "Washington State" and "Washington City, Utah"). There are as many types of locations as there are types of spaces (e.g., "the bottom of screen", "behind the car", "Earth's orbit", etc.), but it is specially relevant in the context of Geography, where the \*Geo\*location ("In which street/road/town I am?") is often much more important than the actual \*Geo\*position ("what are my GPS coordinates?").

The boundaries of Locations are often defined using either dimensional properties (i.e., width, height and depth) or specific shapes (most notably, 2D projections in a geographical space called [Geofences](#)). However, when there are a large amount of locations or these are constantly changing, the boundaries are defined by proximity to the closest point in the [topological skeleton](#) or by the minimum number of logical connections.

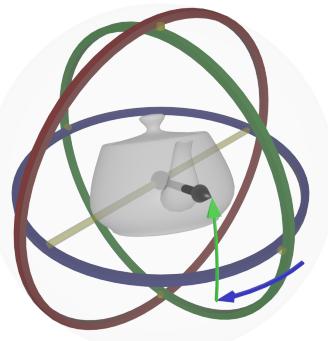
# Chapter 4. Orientation Systems

This section covers a system to accurately describe the orientation of an object relative to the associated reference frame. As with positioning counterparts, these systems provide a vector that needs to be consistently interpreted (so that it can be converted into a rotation matrix), not only to describe the numeric values in the proper sequence, but also to note the units and to specify the type of orientation system to which the values refer.

MOVE THIS REMARK TO ANOTHER PLACE: While orientation systems also have to account for inaccuracies, they are considered less important because they can generally be corrected afterwards (or recalculated using two position vectors) with relative ease.

Not all applications require orientation information to define a Pose.

Euler Angles



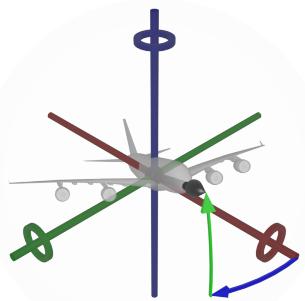
EulerAngles.blend

"The Euler angles are three angles introduced by Leonhard Euler to describe the orientation of a rigid body with respect to a fixed coordinate system." [\(from Wikipedia\)](#)

The angles are generally specified in degrees (in a similar way to longitude/latitude values in Global Positioning Systems), although the internal operations on computers are almost always performed in radians, one axis after another. Usually, the application order of rotation transformations is the inverse of the specification (the Z angle is applied first, then the Y on, and finally, the X one), but it might vary depending on the use case or the hand rule employed.

It is important to note that, since the rotation operations are applied globally and linked together by the application order, if two axes are driven into a parallel configuration, it can generate a [Gimbal Lock](#), resulting in the loss of one degree of freedom. This is usually not a problem when defining simple, discontinuous orientations, but when the use case involves overlapping or interpolating between multiple Euler angles, the result can be negatively affected.

## Aircraft Principal Axes



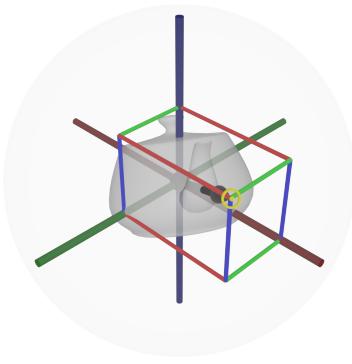
AircraftPrincipledAxes.blend

"Aircraft Principal Axes define the relative (local) rotation of an object, using a plane flying in the +X axis as a reference."

This system defines the orientation of an object as a combination of rotations along the three axes of an aircraft: yaw (or normal) axis, pitch (or transverse) axis and roll (or longitudinal) axis. These axes have a direct correspondence with the X, Y and Z axis of the (right-handed) Euler system and are defined with the same units. However, since these axes are applied locally (i.e., rotating the coordinate system of the object at each step), the order of application becomes irrelevant.

The Aircraft Principled Axes system has the advantage of being very intuitive (once the users fully understand what axis is related to the terms yaw, pitch and roll) and of not being susceptible to [Gimbal Lock](#) issues. On the other hand, this orientation system often requires additional computational power to generate the intermediate rotation matrices (one for each axis with a value different from 0) and, while the image of an airplane can be projected onto other vehicles, it might be difficult to do so with other static elements (e.g., it doesn't make sense to define the "roll angle" of buildings or any other static structures).

## Quaternions\*



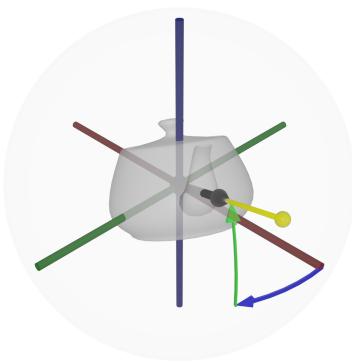
Quaternion.blend

"In computer graphics, a Quaternion is 4D complex number that is used to specify orientations in a 3D space."

In essence, a Quaternion is a mathematical construct with 3 imaginary components ( $i$ ,  $j$  and  $k$ ) and one real component. When it is used to describe 3D orientations, each imaginary component describes the dimension of a **unitary** vector in a particular axis of the space ( $i$ ,  $j$  and  $k$  are assigned to the X, Y and Z axis, respectively) whereas the real component expresses **half** of the rotation around that unitary vector, expressed in radians. However, to ensure that the resulting axial vector is unitary (i.e., its length equals one), a quaternion has to follow the fundamental formula  $i^2 = j^2 = k^2 = i \cdot j \cdot k = -1$ .

Due to their mathematical construction and the possibility to interpolate them both [linearly](#) and [spherically](#), most 3D engines use Quaternions internally to orientate and animate compound objects. However, the complex nature and the interdependence between imaginary components, make Quaternions very difficult for most human beings to understand and use, so they are rarely employed in user interfaces or human-readable documents.

## Look-At Systems



LookAtSystem.blend

"A Look-At system enables the definition of orientation relative to another object or position vector."

Similar to Quaternions, Look-At systems use a vector (obtained from the difference of the target position minus the current position) to determine the orientation of an object. After normalizing the vector, it is possible to use its components to create a quaternion and apply the same mathematical operations. However, to properly determine the rotation angle around the axial vector (the real component of a quaternion), it is necessary to also provide an "up" vector to serve as a pivot.

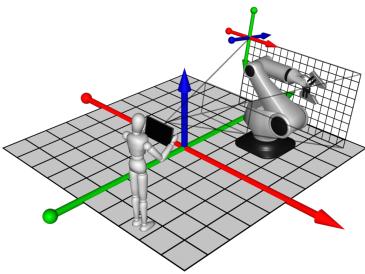
# Chapter 5. Positioning Systems

This section covers a system to accurately describe the position of an object relative to the associated reference frame. The position of an object is a single point in space relative to the origin point of the reference frame. This point is usually placed in the center of mass of the object and provides a simple way to perform other spatial calculations (i.e., distances between objects, travel time, collision detection/avoidance, etc.). In contrast, with a camera, the point could be its focal point.

The objective of positioning systems is to provide a position vector (that is often converted into a translation matrix) as precise as possible within a reference frame. These vectors are often accompanied with an (in)accuracy value to be able to establish an uncertainty threshold for different tasks.

We distinguish the concepts of position and location. Location is a broader term that can be represented in many forms, including textual forms such as the address. While it is possible to define a position using a known location (e.g., "This building is in Tokyo"), this practice often results in imprecise information.

## Local Systems



LocalPositioning.blend

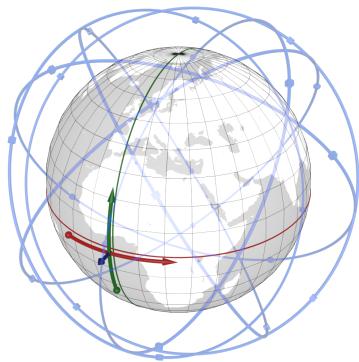
"A Local Positioning System defines the location of objects relative to a Frame based on [Euclidean spaces](#)."

These frames are often defined with an arbitrary point of origin depending on the nature of the subspace to represent. When working with physical spaces or virtual 3D scenes, the point of origin is generally situated in the center of the space (to avoid the limitations of [single-precision floating-point numbers](#)).

However, when operating within 2D spaces with clear boundaries, like screens or documents, the point of origin is normally placed in the top-left corner (due to the graphic systems based on the left-to-right, top-to-bottom writing direction used in most western countries). Needless to say, this makes the transformations between the different frames (i.e., determining what 3D object has the user selected on a 2D screen) a very cumbersome process.

In recent years, advancements in [Indoor Positioning Systems](#) technologies have enabled the precise tracking of real-world elements in relatively large **local** subspaces. Yet, when a use case has more than a single location or the curvature of the Earth becomes an important factor to take into account, using a Global Location System is generally a better option.

## Global Systems



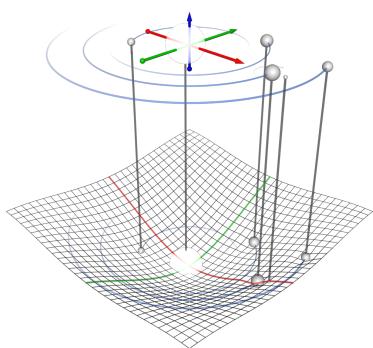
GlobalPositioning.blend

"A Global Positioning System defines the location of objects relative to a Frame based on **spherical spaces**, generally associated with the planet Earth."

As its name implies, a Global Positioning System is defined by a spherical object that establishes the properties of a **Frame** itself (even if the astronomical body is not a perfect sphere). The resulting subspace is delimited in the two horizontal dimensions of the surface of a sphere (**longitude** should only have values between -180 and 180 degrees, whereas the **latitude** values should be within a -90 to 90 degrees) and partially delimited in the vertical dimension (**altitude** values should never be lower than the negative value of the radius of the sphere). As for the point of origin of this subspace, for practical reasons, it is generally placed on an arbitrary point alongside the equator of the sphere (thus, also defining an offset value for the altitude values).

Traditionally, determining the position of an object on the surface of the Earth with any degree of accuracy required cumbersome tools and manual calculations. Fortunately, nowadays, the existence of satellite-based radio-navigation systems like **GPS**, **Galileo** or **NavIC** has greatly simplified the process and -as long as the devices can establish visual contact with three satellites- it is possible to track the position of all kinds of objects on Earth.

## Universal Systems



UniversalPositioning.blend

"A Universal Positioning System defines the location of objects relative to an Inertial Frame based on [Minkowski spaces](#)."

These systems aim to provide a more precise and truly unique positioning for objects relative to an inertial point in the physical Universe (generally, the barycenter of the Solar System). However, since the Minkowski spaces are defined by the rules of [Special Relativity](#), the very subspaces are "curved" by [Lorentz Transformations](#) and any traversal is limited by the [Speed of Light](#).

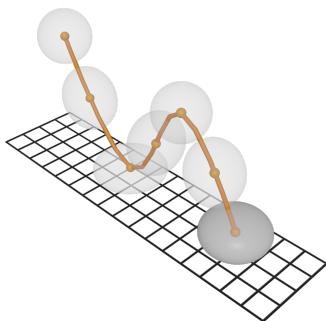
Needless to say, the extremely complex calculations that these positioning systems require relegating them to applications related with interplanetary travel and communications. For example, the SPICE framework created by the NASA's Planetary Science Division operates with both the [J2000](#) and [ICRF Inertial Frames](#) to calculate transfer orbits between bodies of the Solar System.

# Chapter 6. Time-related Concepts

While, by definition, a pose defines the position and orientation of an object at a particular point in time, there are many applications that require the use of temporal sequences of poses. Properly taking into account the temporal dimension requires consideration of additional factors like (moment of) inertia, mass, changes in shape and, in extreme cases, even the variations in the Earth's gravity field.

To help represent this complexity, the following list of terms is intended to offer a basic introduction to the topic.

## Animation



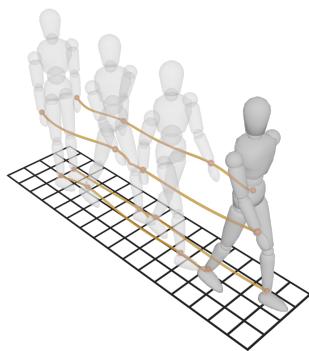
[Animation.blend](#)

**"Animation is a method to create the illusion of movement through a collection of still images."**

In computer graphics, animation is generally simulated by modifying the properties of an object (including its position, rotation, scale, material colors, etc.) over a period of time (or timeline). Since complex deformations require a large number of physics calculations, most animation systems either operate with properties independently (i.e, separating position, orientation and scale) or define skeleton-based systems to alter the geometry of the object in a controllable way. In recent years, however, many 3D engines incorporate procedural subsystems to simulate advanced animations (such as explosions, wind systems, collision deformations, etc) in real-time, with relatively high degree of precision.

Internally, each change in properties is stored into an "animation key", and when there is more than one key over time, an "animation curve" is generated to specify how to interpolate between them. A collection of curves is called an "animation clip" and can be associated to a given action or event.

## Motion



## Motion.blend

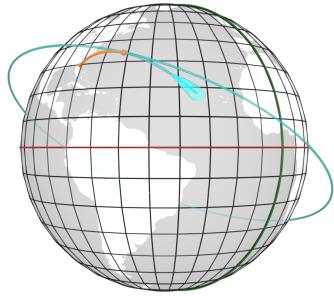
**"A Motion is a type of Animation that only defines the movement (position+orientation keys) of objects."**

In many use cases, it is possible to simplify complex animations by segmenting an object (generally, using a skeleton structure) and reducing the types of keys to just position and orientation (creating animation curves known as Motion Paths). This idea of only taking into consideration the movement of different parts of an object is the basis of [motion capture](#) techniques; a series of technologies that, nowadays, can even [record subtle facial expressions of human beings](#).

Another interesting point of view is that motions can also be defined as transitions between different poses of an object. In this way, instead of having to define a single sequence of animation keys, it is possible to "jump" between different poses by merely interpolating between them whenever necessary (something especially useful when dealing with real-time camera -motion- tracking systems).

It is important to note that a motion between two poses also generates a direction vector and an attitude (orientation relative to that direction vector).

## Trajectory



[Trajectory.blend](#)

"A trajectory is a precalculated Motion Path that attempts to describe the future movement of an object."

While motion paths describe the actual movements over time, in many use cases it is imperative to also be able to predict the future movement of an object (e.g., to avoid collisions or reach a location/orbit with a very specific speed and orientation). These special motion paths are called **Trajectories** and are usually calculated by simply taking into consideration the inertia of an object.

This is especially important for objects placed in a stable trajectories relative to others objects (usually, astronomical bodies), because if those trajectories are entirely predictable, it is possible to create an [Ephemeris](#) system to rapidly calculate their position at any point in time. Additionally, if a predictable trajectory is regularly repeated over time, it can also be called a stable [Orbit](#).

## Gesture



Gesture.blend

**"A Gesture is a Pose or Motion used to convey a non-vocal message."**

Gestures are a form of communication that involve the positioning/movement of a part of the body in a predetermined way to express a particular concept. And although this type of communication is used by many living beings, humans have used them to develop complete sign languages or to serve as a method of identification. Some basic gestures even allow people to overcome linguistic barriers and create a culture around specific gestures.

Nevertheless, since messages conveyed by gestures require both the issuer to be able to make the gestures and the receiver to be able to interpret them correctly, both the communication channel (the physical space) and the meaning of each gesture has to be previously defined to avoid misunderstandings.

It is important to clarify that gestures can also be conveyed by a visual representations (e.g., the Unicode symbol U+1F44C "⌚") or with robotic systems that emulate the body structure and movements of the living beings (which is one of the basis of the Animal-Robot Interaction field).

# Chapter 7. The GeoPose Standard

This section describes the key elements of the GeoPose standard, especially the conceptual and logical models, and the implementation targets which have been derived from the logical model. The development of the standard has been led by a number of use cases and use case domains, as summarised in the diagram below.

INSERT the figure and explain it here or simply point the reader of the reviewers guide to that section?

## 7.1. Conceptual Model

The GeoPose Conceptual Model consists of linked definitions of terms denoting concepts expressed in the GeoPose Logical Model and structural data unit specifications for the implementation targets.

The Conceptual Model is defined in [this section of the GeoPose Standard](#).

**NOTE** Change the link above to an anchor, not to the .adoc file

## 7.2. Logical Model

While the Conceptual Model outlines the component terms and relationships in the standard, the Logical Model precisely models the classes and their relationships.

The Conceptual Model describes a (non-normative) domain of discourse for terms used in defining a precise Logical Model (normative) expressed as a Unified Modeling Language (UML) [ref] class diagram.

The scope of the Logical Model is a subset of the scope of the Conceptual Model. The scope of the implementation targets is a subset of the scope of the Logical Model.

The Implementation Targets are mutually independent implementations of subsets of the Logical Model.

## 7.3. Encodings for Implementation

Christine proposes we use some or all of this text (from the spec) as an introduction to this chapter.

The core abstraction in the OGC GeoPose Standard is the Frame Transform. This 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.

Implementation of position and orientation encodings that are compliant with the OGC GeoPose standard is accomplished by following the standard's requirements for one or more of the eight

data objects referred to in the specification as the "Standardization Targets".

#### *Summary of the Eight OGC GeoPose Standardization Targets:*

Core:

- The two Basic GeoPose targets are simple and concise – no options. They satisfy most use case requirements and assume a local tangent plane ENU frame derived from WGS84.
- An Advanced GeoPose target supports more complex use cases where the outer geographic reference frame is not LTP-ENU and/or a valid time is needed.

Composite:

- The Chain GeoPose target provides additional flexibility with multiple intermediate frames or specific coordinate reference systems as needed.
- The Frame Graph target supports the full structure need to represent networks of reference frames that arise with the use of multiple and linked location technologies.
- The three (Time) Sequence targets support the packaging of fixed-length time series of GeoPoses and the payload data objects for open-ended GeoPose streams.

Depending on the use case and requirements, a developer can implement support for one or more of these targets.

There are automated tests that can be used to determine whether an actual JSON-encoded GeoPose data object conforms to the standard.

**NOTE**

This is where we explain the rationale for the eight standardization targets that were chosen.

In the majority of use cases, requirements are met by using either:

- **Basic-Euler** GeoPose encoding when orientation is in Euler angles
- **Basic-Quaternion** GeoPose encoding when orientation is in quaternion

The reason that there are two versions of Basic GeoPose is that some developers prefer a human-readable encoding. In these cases, the Basic-Euler is chosen. In other use cases, orientation by quaternion is preferred.

The two differences between Basic GeoPose and Advanced GeoPose is that, first, in Advanced GeoPose, the developer can specify an outer geographic reference frame other than LTP-ENU. In addition, in the Advanced GeoPose encoding, a single time stamp can be provided. The time stamp pertains only to the single encoding so one of the Composite GeoPose encodings is not needed.

The three Composite GeoPose encodings are designed for when there are linked and sequential GeoPoses. The Chain GeoPose is a linear set of linked poses. The Graph GeoPose is used when there are linked poses but not necessarily in a linear sequence.

For time series poses with constant time spacing, the developer will choose to use the Regular Timeseries GeoPose encoding. When there is a per-GeoPose time stamp that is not at a regular

interval, the developer will choose to use the Irregular Timeseries GeoPose encoding. Finally, in use cases that do not have a pre-defined end time (also referred to as an open-ended sequence of time-stamped GeoPoses), the developer will specify the Stream GeoPose encoding.

# Chapter 8. OGC GeoPose in Context

This section we discuss the place of GeoPose in the world - how GeoPose is situated in the landscape of standards, and the opportunities for GeoPose to standardise the interaction between standards which manage some representation of geographically anchored position and orientation.

In this section of the reviewer's guide, we list the Standards Development Organizations (SDOs) and standards that specify [\[refer to the GeoPose implementation targets in the draft spec\]](#)[a GeoPose implementation target] as a data format. As a convention for the remainder of this section, we use the term "GeoPose" as a shorthand for any implementation target.

The key question this section will answer is where and how GeoPose fits into the landscape of standards. By examining some of the relevant standards| this section illustrates the gaps which GeoPose fills.

There are many existing and emerging standards for position and orientation information. They have emerged from requirements defined in different industries: aviation, planetary sciences, maritime, robotics, autonomous driving, satellite positioning and aerospace, to name a few. There is good practice in commercial and other domains for expressing the position and orientation of entities in all these fields. These existing standards cover different scales, for different purposes, different information environment: sometimes graphical, sometimes geospatial.

## 8.1. OGC GeoPose connects objects to their representation

There are conceptual and actual data pipelines that connect the real world and the objects in it with the representations in information and graphics systems. A number of the critical standards define how those pipelines are developed and interoperate or fit together.

In a standard Web browser, information is displayed on a plane. There is a need for a standard to represent information retrieved from the Web on the 2D display plane in a manner that is sufficiently fast to provide XR experiences. W3C WebXR focuses on this need.

In order to establish this data flow, there is a need in real graphics systems to locate those objects within a 3D local stage (or scene) so that when the user's head or perceived objects move within that "stage", the graphics systems can address those movements and changes correctly. Khronos OpenXR focuses on that stage of the pipeline.

On the other side, the OGC has been working on how sensor systems measure these changes in position and orientation. How does a system model the sensor that's capturing all the data about the features (e.g. objects) in its environment, including where they are and how the system represents them in a local 2D or 3D environment? OGC Sensor Web Enablement, particularly Observations & Measurements and SensorML, addresses these needs.

Each of these stages in the pipeline need to exchange data between themselves. How do you get the position and orientation of anything from anywhere to anywhere, into and out of these interactive environments? That's where GeoPose comes in. GeoPose defines the data structure(s) to pass position and orientation information between elements in the pipeline.

## 8.2. OGC GeoPose in the Landscape of Standards

The primary source of inspiration for GeoPose was the NASA SPICE framework because it is able to cover any scale from interplanetary and interstellar to specific local objects. NASA designed SPICE to address significant challenges in looking at both ephemeris objects (fixed, or on predictable paths) and objects that have changeable positions and orientations such as satellites, cameras, and other sensors. Representing different frames for these objects and being able to transform between them is really useful. SPICE is a formalism that is much larger than one needs for a simple or basic implementation | but an incredibly appropriate foundation from which the SWG was inspired.

OGC Moving Features was also taken into account when GeoPose was designed. Although it describes object position and orientation, Moving Features (MF) is focused on a particular set of use cases with an emphasis on sensor streams, digital exhausts | and location information (usually GPS) coming off of vehicles in a municipal environment. It accomplishes this compactly so that the data can be easily incorporated into analytical and visual applications.

OGC Moving Features and GeoPose have distinct roles and are complementary. Moving Features is focused on a local, municipal scale, and rapid streams of measurements. Getting observations in and out of municipal management and other platforms easily and efficiently is one of the roles that GeoPose plays.

The OGC Sensor Web Enablement suite of standards deals with how to work with sensors and getting useful observations out of them.

image::images/landscape-standard-ef0fe.png On the right of this figure is a schematic showing the workflows that are enabled in Observations and Measurements, in Semantic Sensor Networks, and with encodings such as SWE Common that enable transport of sensor outputs (observations). Another important part of these standards, SensorML, models the sensor process itself, from an initial environmental stimulus to how a measurement is recorded as an observation and recognized as an observed property of a real world object.

If this is a directed sensor (e.g. camera), orientation is an essential aspect of the sensor model. The result potentially includes the positions and orientations of both the sensor / platform and any observed entities in the world, although the sensor position and orientation may be secondary to the primary objective of observing the positions and orientations of these observed entities, e.g. cars. GeoPose permits systems to get the position and orientation in and out of SWE-compliant platforms or devices without losing any resolution or introducing delays.

Pose is essential for combining physical and digital entities in visual scenes for them to be used by a service or a user, particularly if entities are being brought into a scene from very different source contexts, and regardless of where they are in space.

Khronos OpenXR handles poses, particularly within specific spaces (frames of reference). It defines a set of reference spaces (view, local and stage); and specifies the model in which graphics hardware can use the pose in rendering objects. Within a particular graphical system, it is effective but GeoPose adds the capability to bring in a pose from any source in any frame of reference.

GeoPose can also relate the frame of reference of a Web browser window to a virtual world or the real world.

Geocentric (earth-based) position and orientation are the basis for all these integrations. OGC GeoPose provides that usable common ground, both the geospatial expertise that OGC has cultivated for many years and digital representation of physical space as the most common denominator among all these systems and representations.

To summarize, there are a number of well-developed standards for position and orientation. What these lack is a means for position and orientation information to be passed between them in a manner that is independent of graphical system, applications scene, frame of reference, and technology. OGC GeoPose offers portability of information between all these domains and systems.

The approaches to this issue that have been published in other standards prior to introduction of GeoPose appear in the tables below.

## 8.3. Standards which Could Reference GeoPose in Normative Clauses

### 8.3.1. OGC Standards

The OGC has many positioning and location standards, some also express orientation. They do so in different scales and with different global and/or local coordinate reference systems. Some also deal with different time scales. However, these standards are not designed for sharing position and orientation.

Some standards (such as OGC CDB) deal with fixed infrastructure, or with somewhat more specialized information, such as KML and IndoorGML. Some deal with expressing location and orientation in very dynamic and real time scales, such as Sensor Web Enablement and Moving Features.

Standard	Graphic/Virtual Context	Local SRS	Geodetic SRS	6DOF: as entity or attributes?	Temporality	Remark
Moving Features	?	Y	Y	Attributes of temporal geometry	Y	
Sensor Web Enablement (SWE)						
CityGML	Y	Y	Y	Y (?)	Y	
IndoorGML		Y	Y			
"CDB (Common Database)"	?	?	?	?	?	
KML			Y			

Standard	Graphic/Virtual Context	Local SRS	Geodetic SRS	6DOF: as entity or attributes?	Temporality	Remark
Observations and Measurements	?	?	?	?	?	
SensorThings API	?	?	?	?	?	
IMDF	?	?	?	?	?	
3D Tiles	Y	Y	Y	"x,y,z+normal"	Y	"3D Tiles is basically a binary, encapsulated glTF with georeferencing. There are efforts to make glTF more ""geospatially friendly"". → include glTF (Khronos Group) in the list."

### 8.3.2. Other SDOs

There are other standards development organizations (SDO's) that deal with location and orientation for graphics. They are compiled in the tables below. Work done in the W3C defines how systems express location and orientation for browsers. The Motion Imagery Standards Board (MISB) has standards for moving cameras. ISO also has sections of its standards in SC 24| such as the X3D standards| that encode orientation and position in graphics. In the Khronos Group| there are standards such as OpenXR and glTF that specify how to form digital assets that encode position and orientation

*Khronos Group*

Standard	Graphic/Virtual Context	Geographicaly-referenced Local SRS	Geodetic CRS	6DOF as entity or attribute?	Temporality
glTF	?	?	?	?	?

<b>Standard</b>	<b>Graphic/Virtual Context</b>	<b>Geographicall y-referenced Local SRS</b>	<b>Geodedic CRS</b>	<b>6DOF as entity or attribute?</b>	<b>Temporality</b>
OpenXR	?	?	?	?	?
OpenVX	?	?	?	?	?

| [This OpenXR Extension for Microsoft Spatial Anchors](#) allows an application to create a spatial anchor| an arbitrary freespace point in the user's physical environment that will then be tracked by the runtime. The runtime should then adjust the position and orientation of that anchor's origin over time as needed| independently of all other spaces and anchors| to ensure that it maintains its original mapping to the real world.

*W3C*

<b>Standard</b>	<b>Graphic/Virtual Context</b>	<b>Geographicall y-referenced Local SRS</b>	<b>Geodedic CRS</b>	<b>6DOF as entity or attribute?</b>	<b>Temporality</b>
Geolocation API	?	?	?	?	?
Browser Sensor Interfaces	?	?	?	?	?
Immersive Web WebXR Device API	?	?	?	?	?

[XRSpace](#) and [XR Pose](#) | An XRSpace represents a virtual coordinate system with an origin that corresponds to a physical location. Spatial data that is requested from the API or given to the API is always expressed in relation to a specific XRSpace at the time of a specific XRFframe. Numeric values such as pose positions are coordinates in that space relative to its origin. The interface is intentionally opaque.

*Motion Imagery Standards Board (MISB)*

<b>Standard</b>	<b>Graphic/Virtual Context</b>	<b>Geographicall y-referenced Local SRS</b>	<b>Geodedic CRS</b>	<b>6DOF as entity or attribute?</b>	<b>Temporality</b>
MISB ST 0601	?	?	?	?	?
MISB ST 0801.5	?	?	?	?	?

*BuildingSmart*

<b>Standard</b>	<b>Graphic/Virtual Context</b>	<b>Geographicall y-referenced Local SRS</b>	<b>Geodedic CRS</b>	<b>6DOF as entity or attribute?</b>	<b>Temporality</b>

IFC	Y	?	Y	No	?
-----	---	---	---	----	---

IfcSite and other IfCProducts permits topologic orientation, but not 6DOF. IfcSite lets users provide the WGS84 location (lat,lng,alt) of "the single geographic reference point for this site "  
[http://standards.buildingsmart.org/MVD/RELEASE/IFC4/ADD2\\_TC1/RV1\\_2/HTML/schema/ifcproductextension/lexical/ifcsite.htm](http://standards.buildingsmart.org/MVD/RELEASE/IFC4/ADD2_TC1/RV1_2/HTML/schema/ifcproductextension/lexical/ifcsite.htm) For orientation they refer to the concept of "true north": "The world coordinate system, established at the IfcProject.RepresentationContexts, may include a definition of the true north within the XY plane of the world coordinate system, if provided, it can be obtained at IfcGeometricRepresentationContext.TrueNorth."

ASTM

Standard	Graphic/Virtual Context	Geographicall y-referenced Local SRS	Geodetic CRS	6DOF as entity or attribute?	Temporality
E57	<a href="#">defines fifteen features that cover the core capabilities of the E57 format</a>	?	?	?	?

There are also specifications (standards) that are developed for and used by industries/domains.

### 8.3.3. Space Science

The Observation Geometry System NASA uses for Space Science Missions is called SPICE. A tutorial presentation about SPICE is available [here](#).

NASA

Standard	Relevant Section	Quote the Text
SPICE	<a href="#">Frame Kernel</a>	

Also | must create a table dedicated to IEEE Standards. What are the IEEE standards?

What about ISO standards?

This URL is a convenient place to view many space data standards URL:  
<http://spacedatastandards.org/>

## 8.4. Software that Use or Generate Geospatially-anchored Position and Orientation

This section of the reviewer's guide captures information about commercial software and open source software and libraries that use or generate geospatially-anchored poses. It illustrates the diverse ways that geospatially-anchored poses are stored and represented.

The exercise shows the high potential to increase interoperability between a wide range of existing solutions when a developer chooses to implement the OGC GeoPose standard.

The table below documents, in a structured format, the features and functions of solutions identified at the time of publication of this guide.

Since new software is being introduced to address the requirements of use cases covered by GeoPose, this section could be maintained/updated periodically. If you have information to contribute to this section, or have recommendations and questions, please create an issue in [this repo](#).

Com pan y or Ope n Sou rce?	Pro duct or Serv	Ope n ice Na me	"Wh en this solu tion offe rs, gen erat es or uses pos e, is the pos e (A) geos pati ally- anc hor ed or (B) doe s it use an inte rnal ly- defi ned (loc al) Fra me of Refe renc e?"	Doe s this solu tion use a stati c spat ial refe renc e syst em? Can the ado pter spec ify thei r SRS ?	Plea se pro vide deta ut the spat ial refe renc e syst em use d in this syst em	"In this solu tion, how is abo ut the spat ial refe renc e syst em Can the ado pter spec ify thei r SRS ?	"In this solu tion, how are orie ntat ion and rota tion repr ese nted ?"	"In this solu tion, how are orie ntat ion and rota tion repr ese nted ?"	"If tem por al info rmation is info asso rma ciat tion asso ciat ion repr ese nted ?"	Com men ts
---	---------------------------	-----------------------------	--	--	---	--	---	---	---	------------------

			Geo	Inte					Glo	Loc			yes=		
			Spat	rnal					ball	ally			Gre		
			ially	ly-					y				en		
			-anc	defi					(lati						
			hor	ned					tude						
			ed	(loc					and						
			FoR	al)					long						
			FoR	FoR					itud						
									e)						
Awa	Web		Bot			Stati		WG		Glo				Cam	
ya	Vide		h			c		S84		ball				era	
Tea	o		are			spat				y				orie	
m	Map		poss			ial			(lati					ntat	
Soft	Trac		ible			refe			tude					ion	
war	ks		-			renc			and					is	
e			eith			e			long					sam	
Ltd			er			syst			itud					pled	
			cam			em			e)					peri	
			era											odic	
			hea											ally	
			ding											and	
			or											inte	
			mov											rme	
			ing											diat	
			obje											e	
			ct											valu	
			hea											es	
			ding											can	
			wit											be	
			h											calc	
			cam											ulat	
			era											ed	
			yaw											by	
			(fro											interpol	
			m											ation	
			hea												
			ding	)											

Mag ic Lea p	ML1	?????	?	Stati c spat ial refe renc e syst em							Qua tern ions				
HER E Tec hno logi es	Live Sigh t			Stati c spat ial refe renc e syst em			Glo ball y (lati tude and long itud e)			"Ya w, pitc h and roll"			time sta mp		

Flight Safety	Professional				Statistical spatial reference system	WG S84	"Global ball			"Yaw,	"Position
Interventional	Pilot Training						"Latitude			"Pitch	"Change
							"Longitude			"Roll	"Wit
							"Azimuth			"Quaternions	"Time
							"Euler angles"			"Angular velocity"	"But the tem
							"Angular positions"			"Information"	"Por
							"Relative positions"			"Saved"	"Saved"
							"Moving objects"				
							"Moving objects based on user controls"				

Epic Games	Unreal Engine	Both: A local frame of reference which is itself geospatially anchored	Spatial reference system is defined for each use	"Users can choose the CRS or their choice, as long as they have a WKUT or EPSG code."	Could be both product and data base of projects and geoids	"Yaw, pitch and roll, Quaternions, Euler Angles"	May be integrated into a single solution	Using animation
Arvizio Inc.	Arvizio Immerse 3D	It could be both depending on data type and specific project	Spatial reference system is defined for each use	The product contains extensive and definable data base of projections and geoids	Could be both product and data base of projects and geoids	"Yaw, pitch and roll"	May be integrated into a single solution	Using animation

"Cesium, Inc."	Cesium Inc.				Static spatial reference system	WG S84	"EP SG:4978 (earth-centered/earth-fixed). For precision reasons, keep both local and global transforms for data (location and rotation)."			"3D Tiles data captures the information using the standard graphic approach - transformation matrices. Additionally, optimization beyond transformation matrices (e.g., quaternions, healing).		"Cesium JS can display time-dynamic data provided as CZML or KMZ via API. The data contains samples of position over time and CesiumJS uses interpolation to create the complete path.
----------------	-------------	--	--	--	---------------------------------	--------	---	--	--	--	--	--

Hex ago n	Luci adF usio n 202 0.1 and Luci adR IA 202 0.1			Spat ial refe renc e syst em is defi ned for eac h use	"We sup port any spat ial refe renc e syst em for mod els. For the wor ld, we typi call y use EPS G:49 78 (geo cent ric refe renc e)"	Glo ball y (lati tude and long itud e)		Eule r Ang les
-----------------	--	--	--	---	--	--	--	-------------------------

Leica	"Leica		Bothead		Statistic		ECF		Globally		"Quater		Tim	
a	ca		dep		spatial		or		(lati		nio		esta	
Geo	Imaging		endi		referenc		Local		tude		Eule		mp	
syst	ging		ng		e				and		r			
ems	Total		on		system				longitu		Ang			
AG	lstat		the						de)		les"			
part	ion /		solu											
of	Mul		tion											
Hex	tista		(											
ago	tion,		example:for											
n	Tilted &		total											
	Imaging		station											
	GNS		imaging											
	S"		camera											
			is											
			local											
			)											

Hex	my					Spat	"Mu	Glo			"Ya		App	App		
ago	VR					ial	ltipl	ball			w,		licat	licat		
n	XRT					refe	e	y			pitc		ion	ion		
AB /	oolk					renc	syst	(lati			h		defi	defi		
my	it					e	ems	tude			and		ned	ned		
VR	(SD					syst	dep	and			roll,					
Soft	K)					em	endi	long			Qua					
war						is	ng	itud			tern					
e AS						defi	on	e)			ions					
						ned	use				"					
						for	case									
						each	,									
						use	eith									
							er									
							data									
							dep									
							end									
							ent									
							or									
							appl									
							icati									
							on									
							defi									
							ned.									
						"										

Esri	Oriented Imagery					Spatial reference system is defined for each use	It can be any spatial reference system.	Globe (latitude and longitude)			"Yaw, pitch and roll, Euler Angles, Euler Angles with two rotations about z axis and one about x axis in order z-x-z"			Acquisition Dataparameter information
------	------------------	--	--	--	--	--	---	--------------------------------	--	--	---	--	--	---------------------------------------

Ecer e	GN OSI S	"No rma lly geos pati ally anc hor ed, but loca l tran sfor mat ions can be anc hor ed to thos e geos pati al anc hors "	"No rma lly WG S84 is use d, but we wan t to imp rove sup port for diff ere nt epo chs / real izati ons of WG S84, and othe r CRS can be con vert ed to our inte rnal WG S84 repr ese ntat ion as	WG S84	Glo ball y (lati tude and long itud e)	"Ya w, pitc h and roll, Qua tern ions ,	"Not curr entl y, but ther e cert ainl y is valu e in doin g so, tho ugh it coul d be pro vide d alon gsid e the pos e."
-----------	----------------	---	--	-----------	--	--	---

Graphmetrix Inc.	Trinpod					Static spatial reference system	WG S84	Events are used from start to finish		Quaternions			Events with start time/location and end time/location
								had an event base d reference back to lat/long/ elev	to capture object state and motion using g nested oriented reference frames that ultimately resolved to WG S84 at any nesting level			are used for all changes to entities	

Nor weg ian	Bor der	Yes	The Geo Pos e libr ary mai ntai ns an esti mat e of the geos pati al posi tion and orie ntat ion ion of a real -wo rld anc hor ed loca l fra me of refe renc e.	"Th e loca l cart esia n coor dina te syst em (fra me of geos refe renc e) in the AR sess ion par allel to the loca l tang ent plan e of the WG S84 ellip soid and has east nort h up axis, in addi tion ther e is	ther e is a geo des y libr ary that allo ws the use of geos pati al data sets usin g diff ere nt SRS' s	WG S84	"lati tude ,	"tw o cart long itud e and altit ude abo ve/b elo w the refe renc e ellip soid in met ers"	"tw o cart long itud e and altit ude abo ve/b elo w the refe renc e ellip soid in met ers"	Qua tern ions			Geo Pos e is estim ated cont inou sly base d on vari ous sens or data (sen sor fusi on) and a phys ical mod el tha real ies on tam psta mps of the mea ssur eme nts tha upd ates the estim e.
-------------------	------------	-----	---	--	--	-----------	--------------------	---	---	---------------------	--	--	--

Fant	Cam	Pro																	
asm	era	pos																	
o	Posi	ed																	
	tion																		
	ing																		
	Stan																		
	dar																		
	d																		

Cesi um	Cesi um	Yes	ECE	loca l				WG S84	"EC EF + lat,l ng, alt"	loca l		Qua tern ion			the orie ntat ion are estim ated base d on a	Not an orig inal acco unt by Cesi um.j
.js	Velo city		F	cart esia						cart esia					dev elop er.	
Orie ntat ionP rop erty				n						n	fra mes				Bas ed on	
										fra mes	of				Jan- typi call y	
										of	refe rence				Erik Vinj	
										refe rence					e	
											rea tem				rea ding	
										tem	som				som	
										som	por ally				of	
										por ally	arr ange				the	
										arr ange	d				docs	
										d	like				suc	
										like	h as				this:	
										h as	a				flig	
										a	flig				ht	
										flig	ht				http ://c	
										ht	traj				esiu	
										traj	ecto				m.c	
										ecto	ry				om/ lear	
										ry					n/ cesi umj	
															s/ ref- doc/	
															Velo city	
															Orie ntat ionP rop erty	

Rob ot	geo gra	Yes	Geo Pos	One can also use use locat l cart esia n fra mes of refe renc e.	It can at leas t han dle UT M and WG S84	WG S84	"W GS8 + 4 UT M	loca l cart (Lat, esia ng, alt) fra mes of refe renc e	Qua tern ion				Rob ots are by thei r nat ure ROS dyn ami c and ROS pro vide s mec on hani sm for Geo Pos e rea stre ami ng	Not an orig inal acco unt by ure ROS dev elop er or user . Bas ed ed Jan- Erik Vinq e rea ding som of the docs <a href="http://docs.r">http://docs.r</a> os.o rg/
-----------	------------	-----	------------	---	---	-----------	--------------------------------	--	--------------------	--	--	--	---	--

Below is a table of companies who publish products about which all relevant information has yet to be captured.

Company	Product Name	Local and/or Geospatial Pose	SRS Variable or Static	Naming Conventions	Data Model Details
Autodesk	Cell in column 2	local	Cell in column 4	Cell in column 5	Cell in column 6
Bentley	Context Capture	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Deeyook	Cell in column 2	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6

Company	Product Name	Local and/or Geospatial Pose	SRS Variable or Static	Naming Conventions	Data Model Details
Esri	ArcGIS Runtime	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Esri	ArcGISARView (built on SceneView)	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Facebook	Scape.io	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Google	Visual Positioning Service	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Google	Maps	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Google	Chrome?	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
HERE Technologies	Visual Positioning Service Proof of Concept with Verizon	Cell in column 3	sub-meter accuracy using an image or video. Proprietary 3D positioning algorithms from HERE analyze images or videos for accurate positioning. <a href="https://t.her.is/2GjHvCf">https://t.her.is/2GjHvCf</a>	Cell in column 5	Cell in column 6
Immersal (now Hexagon)	Cell in column 2	local	Cell in column 4	Cell in column 5	Cell in column 6
Lyft	BlueVision	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Microsoft	Azure Spatial Anchors	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Niantic	Cell in column 2	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
PTC	Vuforia	local	Cell in column 4	Cell in column 5	Cell in column 6

<b>Company</b>	<b>Product Name</b>	<b>Local and/or Geospatial Pose</b>	<b>SRS Variable or Static</b>	<b>Naming Conventions</b>	<b>Data Model Details</b>
SPAR3D	Cell in column 2	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Sturfee	Cell in column 2	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Trimble	Cell in column 2	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Uber	Cell in column 2	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Verses	Cell in column 2	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
vGIS	Cell in column 2	Cell in column 3	Cell in column 4	Cell in column 5	Cell in column 6
Visometry	Vision Lib	Local	Cell in column 4	Cell in column 5	Cell in column 6
Visualix (now acquired)	Cell in column 2	Local	Cell in column 4	Cell in column 5	Cell in column 6

# Annex A: Revision History

Date	Release	Editor	Primary clauses modified	Description
2021-06-15	0.1	C.Perey and J. Morley	all	initial version
2021-09-30	0.9	C.Perey and J. Morley	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)

[n] Web: Author Surname, A.: Title, <http://Website-Url>

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