



# Less is More: Efficient Networked VR Transformation Handling Using Geometric Algebra

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**Abstract.** As shared, collaborative, networked, virtual environments become increasingly popular, various challenges arise regarding the efficient transmission of model and scene transformation data over the network. As user immersion and real-time interactions heavily depend on VR stream synchronization, transmitting the entire data set does not seem a suitable approach, especially for sessions involving a large number of users. Session recording is another momentum-gaining feature of VR applications that also faces the same challenge. The selection of a suitable data format can reduce the occupied volume, while it may also allow effective replication of the VR session and optimized post-processing for analytics and deep-learning algorithms. In this work, we propose two algorithms that can be applied in the context of a networked multiplayer VR session, to efficiently transmit the displacement and orientation data from the users' hand-based VR HMDs. Moreover, we present a novel method for effective VR recording of the data exchanged in such a session. Our algorithms, based on the use of dual-quaternions and multivectors, impact the network consumption rate and are highly effective in scenarios involving multiple users. By sending less data over the network and interpolating the in-between frames locally, we manage to obtain better visual results than current state-of-the-art methods. Lastly, we prove that, for recording purposes, storing less data and interpolating them on-demand yields a data set quantitatively close to the original one.

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## 1. Introduction

The rise of the 5G networks and their augmented capabilities, along with the increasing need for remote working and collaboration, due to the extended pandemic, have influenced the research initiatives in many scientific areas. Virtual Reality (VR) is an area drastically affected by these facts. Rapid technological advancements of the past decades, both on hardware and software level, have enabled VR experts to deliver powerful visualization algorithms, optimized to provide an immersive user experience. VR applications that exploit modern GPU capabilities enable the simulation of high-fidelity content of a great variety. Driven by modern needs and expectations, collaborative, shared virtual environments (CVEs) have been, upon their inception, a highly active research topic [3, 24, 30, 33]. One of the main research objectives regards the immersion of the users that are present and interact within the same virtual environment. Such a context is common and dictated by modern era industries that require frequent and efficient remote communication between people. As safety has become a first priority due to the pandemic, VR has been proven to be a solution that natively addresses many of the challenges posed, while some others require extra effort to be effectively resolved.

One such interesting problem that arises within the context of a VR CVE, is the provisioning of users with the same high quality of experience (QoE) in both single- and multi-player VR sessions. As modern Head-mounted Displays (HMDs) are able to support intensive resource-demanding VR applications, we can deliver high-fidelity and immersive content in single user scenarios, even when the user interacts in real-time with the virtual environment. Such experience cannot be natively and/or efficiently replicated in the context of multi-user scenarios, even by modern game engines. The basic challenge that VR application designers have to overcome regards the exchange of information between the user movements and their actions in real-time. If this information is not efficiently transmitted, the virtual avatars of the users will not be or appear to be in sync. In such cases, this unnatural-feeling caused by the delay between the users actual movements/actions and their visualization, drastically reduces the immersion and, in certain cases, may even make the application incapable to serve its cause, e.g., in VR training applications.

Another interesting problem that experts try to handle deals with session recording. Nowadays, session recording and playback of a single or multi-user VR session has become of increasing importance for the functionality and effectiveness of certain applications. This is especially significant for applications related to training as replaying users actions can serve as an additional and powerful educational tool. As users are allowed to watch and study all actions of a virtual scene, they can identify and learn from their mistakes.

Recording (and replaying) a VR session is not a task that is natively undertaken by modern game engines and therefore most VR applications do not include such a feature by default. Researchers try to determine the optimal way to record and store all events that happen in a VR session where a single or multiple users exist and interact. Their goal is to explore the proper methods and structures of data that must be employed so that they can achieve a real-time logging where the required data storage remains manageable. Ultimately, such recordings are used to enable replaying of a VR session, a feature that many VR applications still lack today.

Current bibliography contains numerous examples of how the VR record and replay features can enhance the functionality of a VR application, especially the ones related to training, by mainly measuring the performance of users. In [1, 14], the authors present randomized controlled trials on the efficacy of VR simulation for medical skills training. In both these works, the VR cohort demonstrates greater improvement in each specific score category and significantly higher satisfaction, compared to the control group. Grantcharov et al. [9] demonstrate in their randomized clinical trial that surgeons who received VR training performed laparoscopic cholecystectomy faster than the control group, showing great improvement in error and economy of movement scores. Ihemedu-Steinke et al. [23] measured the concentration, involvement and enjoyment of users on a virtual automated driving simulator and provided a comparison of those between a VR and a conventional display. The experiment showed a statistically significant result, that in VR all measured variables had higher values. Southgate [35] proposed the use of screen capture video to understand the learning outcomes in virtual reality experiences. Paying attention to attitudinal change, higher order thinking and metacognition, it was shown that this was a viable method for gaining deeper insights into immersive learning. Lahanas et al. [22] presented a novel augmented reality simulator for skills assessment in minimal invasive surgery. Their simulator allows training of surgeons and assessment of their skills, while the completion time, the path length and two specific types of errors are evaluated.

In [21], analysis of the motion of virtual reality users is presented. The authors use the motion captured in virtual environments and perform the analysis in the same environment. A visual analysis system is developed that allows immersive visualization of human motion data. This method enables the examination of behaviours and can find useful patterns and outliers in sessions.

In [25], kinematic analysis of experienced and novice surgeons during robotic teleoperation was performed. The same transformation data with our methods were used in order to assess the skills of the users. However, robotic kits are not capable of fast prototyping of realistic environments and also event data need to be captured from a video camera. Also, replay is only available through cameras and has the drawbacks that are explained in Sect. 4.1.

Sharma et al. [34] presented a framework for video-based objective structured assessment of technical skills. In this framework, motion feature extraction is performed to detect the spatio-temporal interest points (STIPs). After

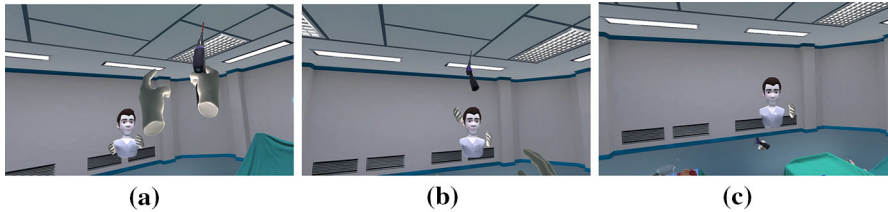


FIGURE 1. Catching a tool in a VR collaborative scenario. **a** A user throws a tool (in our case a medical drill) at another. **b** The object's keyframes, sent by the user that threw it, are interpolated using multivector LERP (see Sect. 3.4) on the receiver's VR engine. **c** The receiver manages to catch the tool, as a result of the effective frame generation that is visualized in his/her HMD

that, the motion classes are learned using  $k$ -means clustering and the STIPs are classified into those classes. Finally, motion class counts, data-driven time windows and sequential motion texture features are computed. An automated video-based assessment tool for surgical skills was proposed in [39]. In this work, a four-step process is developed in order to evaluate the training outcomes in medical schools. These steps are motion class time series generation, feature modelling, feature selection, and classification. In [38], accelerometer data are used in conjunction with video, providing features from multi-modal data. This fusion of video and acceleration features can improve performance for skill assessment. The video data are processed using techniques similar to the two previous papers, while accelerometer data processing is performed by aligning those data with the timeseries computed by the video data. Afterwards, these two kinds of data are combined in order to extract and select useful features and skills assessments are classified using a nearest neighbour classifier.

It becomes apparent from these works and the current research initiatives that the use of VR simulations with the capability of VR recording and replaying, will enhance the learning outcomes of the users, since this functionality enables the replay of sessions and, also, provides data to analyze, with automated tools, the performance of the users. The latter empowers serious game developers to create assessment tools for large-scale real-time evaluations without the need of human labor.

**Our Contribution.** In this work, we propose novel methods to address the two aforementioned problems; A) effective handling of data exchange in multi-user VR sessions and B) efficient recording of user actions in VR sessions, especially for training applications. For both problems, we deploy mathematical tools from geometric algebra (GA) and various (sub)algebras. Our methods rely on the fact that all basic geometric primitives and their transformations used in VR, such as points, planes, lines, translations, rotations and dilations (uniform scalings), can be uniformly represented as *multivectors*, i.e., elements of a suitable geometric algebra such as 3D Projective

(3D PGA) or 3D Conformal Geometric Algebra (3D CGA). Furthermore, we provide an alternative method that utilizes dual quaternions as the representation form of the position and rotation of the users, both for transmission and storing purposes. Our two methods are compared in detail with the current state of the art (SoA), that deploys vectors and quaternions to manage positional and rotational data respectively. The comparison for both problems addressed is accomplished in networks of variable bandwidth capacity, rating from unrestricted networks to ones that are heavily limited. In all cases, we demonstrate that our methods perform equally or outperform SoA, with increased benefit from our methods as the network quality deteriorates (see Sect. 5). Regarding the data exchange problem, handled in Sect. 3, we provide convincing results in a modern game engine and a VR collaborative training scenario (see the video presentation of this work [17] and Fig. 2). Our methods concerning VR recording are described in Sect. 4, where we present evidence that using multivectors and (dual) quaternions as an alternative to the SoA representation forms yields similar results, especially when data interpolation is required.

**Why use Geometric Algebra?** Algebras such as 3D PGA and 3D CGA<sup>1</sup> are showing rapid adaptation to VR implementations due to their ability to represent the commonly used vectors, quaternions and dual-quaternions natively as multivectors. In fact, quaternions and dual-quaternions are contained as a sub-algebra in both these algebras [11]. Therefore, they incorporate all benefits of quaternions and dual-quaternions representations such as artifact minimization in interpolated frames [19]. Furthermore, geometric algebras enable powerful geometric predicates and modules [18], providing, if used with caution, performance which is on par with the current state-of-the-art frameworks [27]. In the past decades, these algebras have proven to be able to solve a variety of problems in various fields, involving inverse kinematics [13] and physics [5]. In conclusion, this work constitutes yet another step towards an effective all-in-one geometric algebra framework for handling VR data streams, with performance that is on par or exceeds current SoA frameworks.

## 2. Basic Mathematical Notation

In the following sections, we provide basic notation and formulas for (dual) quaternions, dual numbers and multivectors representing motors, for the sake of completeness. Similar or more complicated formulas can be obtained via [7, 11, 19] or any other modern book involving dual quaternions and multivectors. We strongly encourage the reader to visit <https://bivector.net> for more information on these beautiful algebras.

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<sup>1</sup>Of course, instead of 3D PGA-CGA one could also employ a, geometric or not, algebra that would allow the representation of motors in a form suitable for interpolation. Determining if such an algebra, non-isomorphic to a sub-algebra of 3D PGA or 3D CGA, exists was not done in the context of this work.

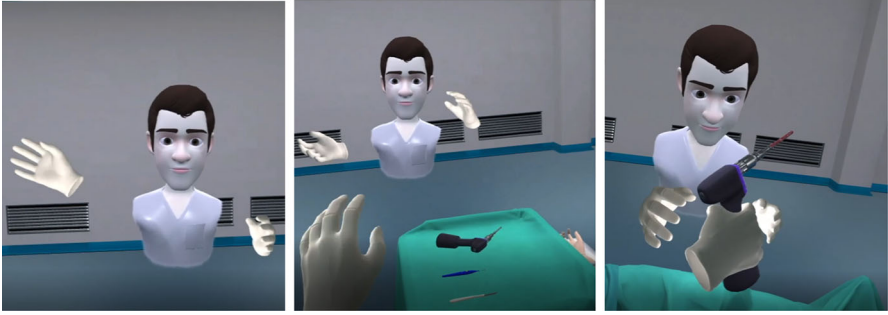


FIGURE 2. Images taken from a modern VR training application that incorporates our proposed interpolation methods for all rigid object transformations as well as hand and avatar movements. It is recommended to see the video presentation of this work [17], to better understand the significance of these figures

## 2.1. Quaternions

The typical form of a quaternion  $q$  is

$$q := q_w + q_x \mathbf{i} + q_y \mathbf{j} + q_z \mathbf{k}, \quad (1)$$

where  $q_w, q_x, q_y, q_z \in \mathbb{R}$  and the imaginary units  $\mathbf{i}, \mathbf{j}, \mathbf{k}$  satisfy the well known identities  $\mathbf{i}^2 = \mathbf{j}^2 = \mathbf{k}^2 = \mathbf{i}\mathbf{j}\mathbf{k} = -1$ . The quaternion  $q$  can also be viewed as a 4-tuple  $(q_w, q_x, q_y, q_z)$ . If  $q_w$  equals 0, the  $q$  is called a *pure quaternion*.

Addition of the quaternion  $q$  to another quaternion

$$p := p_w + p_x \mathbf{i} + p_y \mathbf{j} + p_z \mathbf{k}, \quad (2)$$

is done componentwise, i.e.,

$$q + p := (q_w + p_w) + (q_x + p_x)\mathbf{i} + (q_y + p_y)\mathbf{j} + (q_z + p_z)\mathbf{k}. \quad (3)$$

Multiplication of the two quaternions is carried out as follows:

$$\begin{aligned} qp := & (q_w p_w - q_x p_x - q_y p_y - q_z p_z) + (q_w p_x + p_w q_x + q_y p_z - q_z p_y)\mathbf{i} \\ & + (q_w p_y + p_w q_y + q_z p_x - q_x p_z)\mathbf{j} + (q_w p_z + p_w q_z + q_x p_y - q_y p_x)\mathbf{k}. \end{aligned} \quad (4)$$

by applying the associative property, applying the basic identities and gathering terms. Note that multiplication is generally not commutative.

The conjugate of  $q$  is the quaternion

$$q^* := q_w - q_x \mathbf{i} - q_y \mathbf{j} - q_z \mathbf{k}, \quad (5)$$

and it is easy to verify that

$$(pq)^* = q^* p^*. \quad (6)$$

The norm of  $q$  is defined as

$$|q| := \sqrt{qq^*} = \sqrt{q_w^2 + q_x^2 + q_y^2 + q_z^2}, \quad (7)$$

and its inverse, assuming  $|q| \neq 0$ , is

$$q^{-1} := \frac{q^*}{|q|^2}. \quad (8)$$

If  $|q| = 1$ ,  $q$  is called a *unit quaternion*, and it can be written in the form

$$q = \cos \frac{\theta}{2} + \sin \frac{\theta}{2} (u_x \mathbf{i} + u_y \mathbf{j} + u_z \mathbf{k}), \quad (9)$$

where  $\mathbf{u} := (u_x, u_y, u_z)$  is a unit vector and  $\theta \in [0, \pi]$ . Such quaternions *encapsulate* the rotation of a 3D point  $(p_x, p_y, p_z)$  by angle  $\theta$  around an axis going through the origin in the direction of  $\mathbf{u}$ . Indeed, if we apply the sandwich quaternionic product to the pure quaternion  $p = (0, p_x, p_y, p_z)$  we will obtain the pure quaternion

$$p' := qpq^* = (0, p'_x, p'_y, p'_z), \quad (10)$$

where the  $(p'_x, p'_y, p'_z)$  is the image of the point  $(p_x, p_y, p_z)$  if we applied the aforementioned geometric transformation.

## 2.2. Dual Numbers

A *dual number*  $d$  is defined to be

$$d := a + \epsilon b, \quad (11)$$

where  $a, b$  are elements of some field (usually  $\mathbb{R}$ ) and  $\epsilon$  is a *dual unit*, i.e., it holds that  $\epsilon^2 = 0$ . The elements  $a$  and  $b$  are referred to as the *real* and *dual* part of  $d$ .

Let  $d_i := a_i + \epsilon b_i$ , for  $i \in \{1, 2\}$  be dual numbers. The addition of these dual numbers is performed pairwise, i.e.,

$$d_1 + d_2 := (a_1 + a_2) + \epsilon(b_1 + b_2), \quad (12)$$

and their multiplication is done by applying the associative rule and gathering terms

$$d_1 d_2 := (a_1 + \epsilon b_1)(a_2 + \epsilon b_2) = a_1 a_2 + \epsilon(a_1 b_2 + a_2 b_1), \quad (13)$$

taking into consideration that  $\epsilon^2 = 0$ . Note that the multiplication on the right hand side of the equations above depend on the field where the coefficients  $a_1, b_1, a_2$  and  $b_2$  belong.

The multiplication identity is  $1 + \epsilon 0$  and the multiplicative inverse of  $d = a + \epsilon b$ , when  $a \neq 0$ , is

$$d^{-1} = a^{-1}(1 - \epsilon b a^{-1}). \quad (14)$$

If  $a = 0$ , then  $d = \epsilon b$  has no inverse, which dictates that dual numbers form a ring and not a field.

The conjugate of a dual number  $d = a + \epsilon b$  is the dual number

$$\bar{d} = a - \epsilon b. \quad (15)$$

A really interesting and useful property of dual numbers is that, the function of a dual number  $d = a + \epsilon b$  can be obtained by considering the Taylor expansion at  $a$ , i.e.,

$$f(a + \epsilon b) = f(a) + \epsilon b f'(a) + \frac{1}{2} \epsilon^2 b^2 f''(a) + \dots = f(a) + \epsilon b f'(a). \quad (16)$$

### 2.3. Dual Quaternions

A *dual quaternion* is a dual number  $D = p + \epsilon q$ , where  $p, q$  are quaternions. Regarding dual quaternions,<sup>2</sup> the addition, multiplication and inverse are determined using the forms used in the dual numbers case, taking into consideration that  $\epsilon$  commutes with the imaginary units  $\mathbf{i}, \mathbf{j}$  and  $\mathbf{k}$ . If  $p = (p_w, p_x, p_y, p_z)$  and  $q = (q_w, q_x, q_y, q_z)$ , then  $D$  can also be seen as the vector  $(p_w, p_x, p_y, p_z, q_w, q_x, q_y, q_z)$ .

There are two main conjugates of a dual quaternion  $D = p + \epsilon q$  which are obtained via

- the conjugation of the quaternions parts

$$D^* = p^* + \epsilon q^*, \quad (17)$$

- the conjugation of the dual number form

$$\bar{D} = p - \epsilon q. \quad (18)$$

We can easily verify that  $\overline{D^*} = (\bar{D})^*$ .

If  $a, b$  are quaternions, we denote

$$\langle a, b \rangle := \frac{1}{2}(ab^* + a^*b). \quad (19)$$

The norm of  $D = p + \epsilon q$  is then equal to

$$|D| := \sqrt{D D^*} = \sqrt{|p|^2 + 2\epsilon \langle p, q \rangle} = |p| + \epsilon \frac{\langle p, q \rangle}{|p|^2}. \quad (20)$$

The last equality is obtained by applying 16, for  $f(x) = \sqrt{x}$ . If  $D_1, D_2$  are dual quaternions, it holds that  $|D_1 D_2| = |D_1| |D_2|$ .

A dual quaternion  $D = p + \epsilon q$  that satisfies  $|D| = 1$ , or equivalently  $|p| = 1$  and  $\langle p, q \rangle = 0$ , is called *unit dual quaternion*. Due to these two linear restrictions, the set of unit dual quaternions, seen as vectors, form a 6-dimensional manifold embedded in the 8-dimensional Euclidean space. Also note that if  $D_i$ , for  $i \in \{1, 2\}$ , are unit dual quaternions then  $D_i^{-1} = D_i^*$  and the product  $D_1 D_2$  is also a unit dual quaternion.

A remarkable theorem ([19, Lemma 12 in p12]) is the following.

<sup>2</sup>As *bi-quaternions* gain more momentum, we note here for clarity that they are distinct from dual-quaternions. Indeed, dual quaternions are dual numbers where each coefficient is a quaternion whereas, the bi-quaternions are quaternions where each coefficient is a complex number. A basic difference is that, that apart from the common basic elements  $\{1, \mathbf{i}, \mathbf{j}, \mathbf{k}\}$ , the additional element  $I$  of bi-quaternions satisfies  $I^2 = -1$ , whereas the additional element  $\epsilon$  of the dual-quaternions satisfy  $\epsilon^2 = 0$ .



**Lemma 1.** *Every rigid transformation can be represented by a unit dual quaternion, and conversely, every unit dual quaternion represents a rigid transformation.*

The proof of the lemma is based on the fact that a unit dual quaternion  $D$  can be written in the form  $D = p + \epsilon q$ , where  $p$  is a unit quaternion and  $q = \frac{1}{2}(t_1\mathbf{i} + t_2\mathbf{j} + t_3\mathbf{k})$ , for some vector  $t := (t_1, t_2, t_3)$ . In this case,  $D$  encapsulates the rotation “stored” within  $p$  followed by a translation by  $t$ . Indeed, if take the dual quaternion  $v = (1, 0, 0, 0, 0, v_1, v_2, v_3)$  that corresponds to a point  $v$  and apply the sandwich multiplication by  $D$ , we will obtain

$$v' = Dv\overline{D}^* = (1, 0, 0, 0, 0, v'_1, v'_2, v'_3) \quad (21)$$

where  $(v'_1, v'_2, v'_3)$  is the image of the point  $(v_1, v_2, v_3)$  after applying the rotation encapsulated in  $p$  and then translating by  $t$ .

#### 2.4. Motors in Geometric Algebra

In this section, we provide a brief overview of the 3D PGA or CGA multivectors that arise in our methods. The multivectors studied represent motors, i.e., they are of the form  $M = TR$ , where  $T$  and  $R$  are the multivectors encapsulating a translation and a rotation, respectively. Below, we demonstrate how we can obtain  $T$  and  $R$  from a given  $M$ , and how we can transmute them into the corresponding vector and unit quaternion form that correspond to the same geometric transformations. The later forms are needed by modern game engines to apply the transformation stored in  $M$  to any game object.

- **3D PGA:** In this algebra, the multivector

$$T := 1 - 0.5e_0(t_1e_1 + t_2e_2 + t_3e_3), \quad (22)$$

represents the translation by  $(t_1, t_2, t_3)$  and the multivector

$$R := a + be_{12} + ce_{13} + de_{23}, \quad (23)$$

encapsulates the same rotation with the unit quaternion

$$q := a - d\mathbf{i} + c\mathbf{j} - b\mathbf{k}. \quad (24)$$

In this algebra, it also holds that

$$e_0e_0 = 0, \quad (25)$$

and therefore, if we evaluate the quantity  $e_0M$ , we will obtain the multivector

$$e_0M \equiv e_0TR \equiv (e_0T)R \equiv e_0R. \quad (26)$$

This multivector will be of the form

$$e_0R = ae_0 + be_{012} + ce_{013} + de_{023}, \quad (27)$$

hence we can deduce that

$$R = a + be_{12} + ce_{13} + de_{23}, \quad (28)$$

which corresponds to the quaternion shown in 24. The inverse of  $R$  is the multivector

$$R^{-1} = a - be_{12} - ce_{13} - de_{23}. \quad (29)$$

Since  $M$  and  $R$  are known, we may evaluate  $T$ , as it equals

$$T = MR^{-1} = M(a - be_{12} - ce_{13} - de_{23}) = 1 + xe_{01} + ye_{02} + ze_{03}, \quad (30)$$

and conclude that it corresponds to a translation by  $(-2x, -2y, -2z)$ .

- **3D CGA:** In this algebra, the multivector

$$T = 1 - 0.5(t_1e_1 + t_2e_2 + t_3e_3)(e_4 + e_5) \quad (31)$$

is the multivector that corresponds to a translation by  $(t_1, t_2, t_3)$ . Identical to 3D PGA, the multivector

$$R = a + be_{12} + ce_{13} + de_{23}, \quad (32)$$

encapsulates the same rotation with the unit quaternion

$$q := a - d\mathbf{i} + c\mathbf{j} - b\mathbf{k}. \quad (33)$$

Since  $M = TR$ , it follows from the form of  $T$  that

$$M = TR = R + m, \quad (34)$$

where  $m$  is a multivector that necessarily contains basis elements containing  $e_4$  and  $e_5$  (or their geometric product) that cannot be cancelled out. Therefore, we can obtain  $R$  by keeping the terms of  $M$  that contain *only* the basis vectors  $\{1, e_1, e_2, e_3, e_{12}, e_{23}, e_{13}\}$ . Having determined  $R$  and given  $M$  is known, we evaluate  $R^{-1}$  using 29 and determine  $T$  using

$$T = MR^{-1}. \quad (35)$$

Assuming  $T$  is normalized (otherwise we normalize it), we may extract the corresponding translation vector  $(t_1, t_2, t_3)$  from the quantity  $T(e_5 - e_4)$ , as it holds that

$$T(e_5 - e_4) = t_1e_1 + t_2e_2 + t_3e_3. \quad (36)$$

The conversion of  $R$  to quaternion is identical with the case of 3D PGA above.

### 3. Data Transmission in Multi-user Collaborative VR Sessions

In this section, we consider the transmission of a user's data to the rest of the users, in the context of a multi-user VR collaborative session. The information that is necessarily relayed over the network involves the users interactions through the hand-based HMD controllers such as *displacement data* (e.g., translation and rotation of the controller) within specific time intervals and button-press events. Since the VR rendering engine is typically different for each user, it is crucial to efficiently relay the data of one user to the rest of the users' VR engines, in a synchronized manner. If done correctly [36], all users will be synchronized and actions between users, such as exchanging objects or even playing tennis, can be accurately performed. An inefficient transmission of this information will cause each user's virtual world to depict the rest of the users with increased latency and therefore, collaboration will no longer be possible or feel natural.

To better understand the source of this problem, let us initially consider the pipeline of the data from a user to the rest. When the user moves the hand-based controllers of his HMD, the hardware initially detects the movement type and logs it, in various time intervals based on the user's or developer's preferences. This logged movement, that is either a translation and/or a rotation, is constantly transcoded into a suitable format and relayed to the VR application and rendered as a corresponding action, e.g., hand movement, object transformation or some action. The controller's data format to be transmitted to the rendering engine affects the overall performance and quality of experience (QoE) and poses challenges that must be addressed. These challenges involve keeping the latency between the movement of the controller and its respective visualization in the HMD below a certain threshold that will not break the user's immersion. Furthermore, the information must be relayed efficiently such that a continuous movement of the controller results in a smooth jitter-less outcome in the VR environment. Such challenges heavily depend on the implementation details regarding the communication channel that handles the way that position and rotation of the controller is relayed, as well as the choice of a suitable interpolation technique. The displacement data are transmitted at discrete time intervals, approximately 20–40 times per second. To maintain a high frame-per-second scenery in the VR, multiple in-between frames must be created on-the-fly by the appropriate tweening algorithm. An efficient algorithm will allow the generation of natural flow frames while requiring fewer intermediate keyframes. Such algorithms will help reduce (a) bandwidth usage between the HMD and the rendering engine and (b) CPU-strain, resulting in lower energy consumption as well as lower latency issues in bandwidth-restricted networks. Moreover, HMDs with controllers of limited frequency will still be able to deliver the same results as more expensive HMDs.

### 3.1. State of the Art

The current SoA methods regarding the format used to transmit the displacement data mainly involves the use of 3D vectors for translation and quaternions for rotation data. Modern game engines such as Unity3D and Unreal Engine, have these representation forms already built within their frameworks. The dominance of these forms is based on the fact that they require very few floating point numbers to be represented (3 and 4 respectively) and their ability to support fast and efficient interpolations. Specifically, 3D vectors are usually linearly interpolated, where as the SLERP method is usually used for quaternion blending. In some engines, such as Unity3D, rotations are sometimes provided in terms of Euler angles, but for interpolation needs, they are internally transformed to their quaternion equivalents.

Based on the current SoA forms, the controllers of a VR HMD log their current position  $v = (v_x, v_y, v_z)$  at each time step with respect to a point they consider as the origin. Their rotation is also stored, as a unit quaternion  $q = (q_w, q_x, q_y, q_z) = q_w + q_x\mathbf{i} + q_y\mathbf{j} + q_z\mathbf{k}$ . The use of unit quaternions revolutionized graphics as it provided a convenient, minimal way to represent

rotations, while avoiding known problems (e.g., gimbal lock) of other representation forms such as Euler angles [19]. The ways to change between unit quaternions and other forms representing the same rotation, such as rotation matrices and Euler angles, are summarized in [4].

The interpolation of the 3D vectors containing the positional data is done linearly, i.e., given  $v$  and  $w$  vectors we may generate the intermediate vectors  $(1 - a)v + aw$ , for as many  $a \in [0, 1]$  as needed. Given the unit quaternions  $q$  and  $r$  the intermediate quaternions are evaluated using the SLERP blending, i.e., we evaluate  $q(q^{-1}r)^a$ , for as many  $a \in [0, 1]$  as needed, like before. If these intermediate quaternions are applied to a point  $p$ , the image of  $p$ , as  $a$  goes from 0 to 1, has a uniform angular velocity around a fixed rotation axis, which results in a smooth rotation of objects and animated models.

### 3.2. Room for Improvements

Graphics courses worldwide mention quaternions as the next evolution step of Euler angles; a step that simplified things and amended interpolation problems without adding too much overhead in the process. Despite it being widespread, the combined use of vectors and quaternions does not come without limitations.

A drawback that often arises lies in the fact that the simultaneous linear interpolation of the vectors with the SLERP interpolation of the quaternions applied to rigid objects does not always yield smooth, natural looking results in VR. This is empirically observed on various objects, depending on the movement the user *expects* to see when moving the controllers. Such *artifacts* usually require the developer's intervention to be amended, usually by demanding more intermediate displacements from the controller to be sent, i.e., by introducing more non-interpolated keyframes. This results mainly in the increase of bandwidth required as more information must be sent back and forth between the rendering engine and the input device, causing a hindrance in the networking layer. Multiplayer VR applications, that heavily rely on the input of multiple users on the same rendering engine for multiple objects, are influenced even more, when such a need arises. Furthermore, the problem is intensified if the rendering application resides on a cloud or edge node; such scenarios are becoming increasingly more common as they are accelerated by the advancements of 5G networks and the relative functionalities they provide.

### 3.3. Proposed Method Based on Dual Quaternions

In the past few years, graphics specialists have shown that dual quaternions can be a viable alternative and improvement over quaternions, as they allow us to unify the translation and rotation data into a single entity. Dual quaternions are created by quaternions if dual numbers are used instead of real numbers as coefficients, i.e., they are of the form  $d := A + \epsilon B$ , where  $A$  and  $B$  are ordinary quaternions and  $\epsilon$  is the *dual unit*, an element that commutes with every element and satisfies  $\epsilon^2 = 0$  [20]. A subset of these entities, called *unit dual quaternions*, are indeed isomorphic to the transformation of

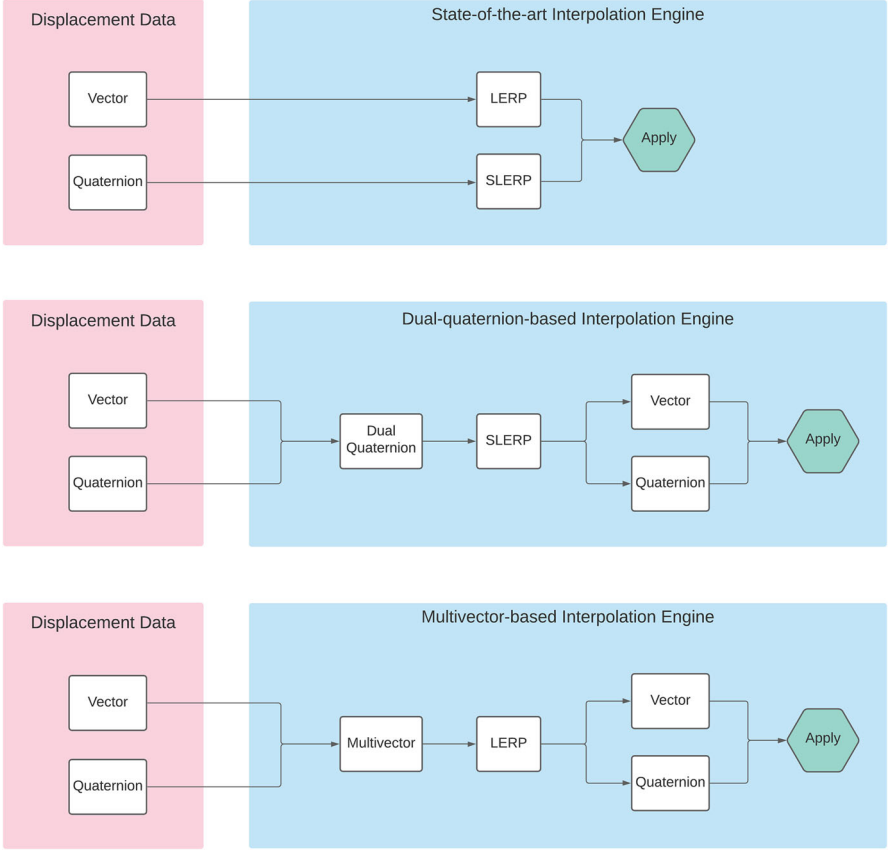


FIGURE 3. Algorithm layout of the different interpolation engines used to generate intermediate frames

a rigid body. A clear advantage of using dual quaternions is the fact that we only need one framework to maintain and that applying the encapsulated information to a single point requires a simple sandwich operator. Moreover, the rotation stored in the unit dual quaternion  $A + \epsilon B$  can be easily extracted as the quaternion  $r := A$  is the unit quaternion that amounts to the same rotation. Furthermore, if  $B^*$  denotes the conjugate quaternion of  $B$ , then  $t := 2AB^*$  is a pure quaternion whose coefficients form the translation vector [20].

Taking advantage of the above, we propose the replacement of the current state-of-the-art sequence (see Fig. 3, Top) with the following (see Fig. 3, Middle). The displacement data of an object is again represented as a vector and a quaternion; in this way, only a total of 7 float values (3 and 4 respectively) need to be transmitted. The VR engine combines them in a dual quaternion [20] and interpolates with the previous state of the object, also stored as a dual quaternion. Depending on the engine's and the user's preferences, a number of in-between frames are generated via SLERP interpolation

[19] of the original and final data. For each dual-quaternion received or generated, we decompose it to a vector and a quaternion and apply them to the object. This step is necessary to take advantage of the built-in optimized mechanisms and GPU implementations of the VR engine.

A major advantage of the proposed method is that we can obtain similar results with the state-of-the-art method by sending less keyframes per second. As an empirical law, we may send 20 displacement data per second with our method to obtain the same quality of generated frames as if we had sent 30 data per second with the current state-of-the-art method. This 33% reduction of required data applies for each user of the VR application, greatly lowering the bandwidth required as more users join. As an example, if  $n$  users participate, the total displacement data required for our method would be  $560n$  bytes per second (20 messages per second  $\times$  7 floats per message  $\times$  4 bytes per double, assuming a classic implementation) as opposed to  $840n$  bytes per second (30 messages per second  $\times$  7 floats per message  $\times$  4 bytes per float) with the default method. The numbers of updates per second mentioned above relate to the case of unrestricted-bandwidth network; for the respective results regarding constrained networks see Sect. 5 and Table 1. This method is incorporated in the MAGES SDK [31] for cooperative VR medical operations, publicly available to be tested for free, as the default transmission method, which is indicative of the performance boost it provides.

The drawbacks of this method is the need to constantly transform dual-quaternions to vector and rotation data after every interpolation step but this performance overhead is tolerable as the extraction of the displacement data is accomplished in a straight-forward way. Also, performing SLERP on a dual quaternion (proposed method) instead of a quaternion (state-of-the-art method) demands more operations per step. The trade-offs between the two methods seem to favor our method, especially in the case of collaborative VR applications.

### 3.4. Proposed Method Based on Multivectors

The proposed method described in Sect. 3.3 was based on the use of dual quaternions and the fact that interpolating them (using SLERP) produced smooth intermediate frames. In this section, we go one step further and suggest the use of multivectors instead of dual-quaternions (see Fig. 3, Bottom). This transition can be done in a straight-forward way if we use multivectors of 3D Conformal (see [11]) or 3D Projective Algebra (see [7] and its updated Chapter 11 in [6]). The interpolation of the resulting multivectors can be accomplished via LERP [10]; if  $M_1$  and  $M_2$  correspond to two consecutive displacement data, then we can generate the in-between multivectors

$$(1 - a)M_1 + aM_2, \quad (37)$$

for as many  $a \in [0, 1]$  as needed (and normalize them if needed). Notice that since we are only applying these displacements to rigid bodies, we may use LERP instead of SLERP (see Fig. 4). For every (normalized) multivector  $M$  received or interpolated, we may now extract the translation vector and rotation quaternion, as shown in Sect. 2.4. Every multivector received or

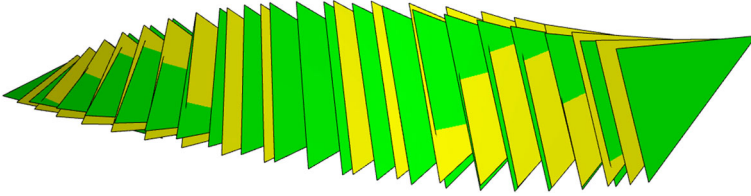


FIGURE 4. A triangular object is interpolated via multivectors. A motor including both a translation and a rotation is applied to the triangle via its mass center. Between the extreme positions of the object, we generate 20 intermediate frames using LERP (yellow) and SLERP (green) interpolation of the multivector. Only minimal differences are spotted between the two outcomes

generated has to be decomposed to a vector and a quaternion in order to be applied to the object, as modern VR Engines natively support only the latter two formats.

The advantage of such a method lies on the fact that we can use LERP blending of multivectors instead of SLERP. This saves as a lot of time and CPU-strain; SLERP interpolation requires the evaluation of a multivector's logarithm, which requires a lot of complex operations [8]. Notice that, LERP is efficient in our case since only rigid objects displacements are transferred via the network; if we wanted to animate skinned models via multivectors it is known that only SLERP can produce jitter-less intermediate frames [19]. Another gain of this proposed method is the ability to incorporate it in an all-in-one GA framework, that will use only multivectors to represent model, deformation and animation data. Such a framework is able to deliver efficient results and embeds powerful modules [18, 27, 28]. In such frameworks, decomposition of multivectors to vectors and quaternions will be redundant, as we can apply the displacement to the object's multivector form via a simple sandwich operation.

The trade-offs of such an implementation are based on the fact that modern VR engines do not natively support multivectors and therefore production ready modules, with basic functions implemented, are almost non-existent. An exception is the Klein C++ module for 3D PGA, found in <http://www.jeremyong.com/klein>; for 3D CGA no such module is available the moment this paper is written. This makes it difficult for GA non-experts to adopt and implement such methods. Furthermore, multivectors require 16 (3D PGA) or 32 (3D CGA) float values to be represented and using unoptimized, usually CPU and not GPU-based, modules to handle them may result in slow rendering. Optimized modules, such as GAALOP [12], can take advantage of the fact that very few of the multivector coordinates are indeed non-zero, as the multivectors involved are always motors, i.e., represent translations and/or rotations, and therefore have specific form. Since the full multivector algebra is not needed for this application, various other approaches exist to achieve performance optimizations (e.g., exploiting the



FIGURE 5. VR record and replay functionality. The point of view of the user replaying a recorded session. The user is able to watch the session from any perspective, as well as pause the replay in order to continue the session on his own

even and odd sub-algebras of motors), even when starting from a formulation of the algorithm as a naive full multivector formula.

## 4. Recording and Replaying in VR

### 4.1. Towards an Efficient VR Recorder

Based on current bibliography, accurate recording of a VR session can be achieved via two methods, mainly differing in what they aim to log. The first method aims to record all users inputs whereas, the second method focuses on the effects that these inputs have on the virtual scene.

As VR advances, the realism of the environments expands as well; trivial interactions such as ripping a plastic case, grabbing a tool or removing the cap from a bottle, have turned to mandatory tasks that greatly add up to the immersive experience. This exponential content expansion is hindering the development of the latter logging method. Therefore, our research revolves around a VR logger that records raw users inputs, as we believe that such an approach suits better to the current growth direction of virtual reality environments.

Opposed to popular recording techniques, we do not take into consideration video recording from cameras that are located in different places within the VR, whether these are static or, for various reasons, in motion. Our decision is based on the fact that such recordings can not allow replaying the session from any other perspective.



Another major disadvantage of such recordings lies on the inability of the user to pause the recording and resume “playing” the session at a certain point. This is caused by the lack of storing values and data that are deeply connected with the current state of the game at that time, but rather superficial snapshots of the VR scene. Without the ability of resume playing at a custom state, players cannot effectively improve their performance in a specific task, unless replaying the whole session.

Raw video recording of the scene also introduces another major drawback. The position of objects and the trigger of various events from the VR is no longer easy to identify and keep track of, without extra effort. Even the use of signal processing algorithms and classification techniques, such as the ones described in [34, 38, 39], will inevitably introduce errors and hinder the monitoring process of such data.

On the other hand, recording the original input data of the users will allow keeping track of the actual raw transformations of objects and events in the scene. This will sequentially enable methods for assessing the performance of users and understanding what the users are actually doing. Eventually, we should be able to create intelligent agents via imitation learning from experts that are able to complete a session “successfully”, and support the users to effectively perform similar tasks accordingly.

Moreover, by avoiding collecting data of high dimensionality, such as the entire state of the virtual world and instead storing low-dimensional information such as the users inputs and triggers, we can obtain valuable analytics even by using simple processing algorithms. One should also notice that the data we choose to record can easily generate the scene by applying the worlds mechanics, while the reverse process would demand sophisticated computer vision algorithms. Lastly, using our recording method, users have the ability to act simultaneously with various recorded interactions and events, a functionality that can be used creatively to increase the pedagogical benefits of various simulations.

## 4.2. Implementation Details

In our proposed recording method, the displacement of all users in the operation is captured, along with their interactions with virtual objects. The voice of each player is recorded individually, including incoming voice in cases of multi-player sessions. Additionally, the actions performed as well as the complete traversal path of the scenegraph [40] are captured. In VR, the objects which the user interacts with might come into contact or interact with other objects, changing the latter’s location or status. Therefore, the transforms of all subsequently affected objects are also recorded.

Four scripts are responsible for recording all the necessary data mentioned above; the `InteractionRecorder`, the `PropagateRecording`, the `GetAudioSamples` and the `RecordingWriter` scripts. The `InteractionRecorder` tracks each user’s head and hands transforms, while the `PropagateRecording` records the status changes of every object that users interact with. All sound related recordings are received by the `GetAudioSamples` script. Finally, the `RecordingWriter` is responsible for writing all recorded interactions, sounds and events

from previous three scripts into respective files. Note that an instance of each script is created for every user of a multi-player session.

We denote the files used to store the transforms of the head, hands and moved objects by **Transform  $X$** , whereas the files that store all the events (*messages*) occurring in the session are denoted by **Messages  $X$** ; in both cases,  $X$  is either **Camera**, **Left Hand**, or **Right Hand**. Finally, the **RecordingInfo** file stores information about the recording, such as the duration of the recording, and is available only for the *owner* of the session, i.e., the (first) user that initiated the session.

Below we present a list of all the data that our proposed VR recorder stores. The data types used are either 3D vectors (for transformation data), events (for various scene events and functionalities) or float (for the time).

- **Left/right hand translation (3D vectors):** Consists of 6 floats (3 for each hand) describing the position of each hand in the virtual environment
- **Left/right hand rotation (3D vectors):** Consists of 6 floats (3 for each hand) describing the rotation of each hand in the virtual environment
- **Camera translation (3D vector):** Consists of 3 floats describing the position of the user's HMD in the VR environment
- **Camera rotation (3D vector):** Consists of 3 floats describing the rotation of the user's head in the VR environment
- **Left/right hand start interaction (event):** The user has started interacting with an object. Consists of the name of the interacted object (string).
- **Left/right hand end interaction (event):** The user has ended interacting with an object. Consists of the name of the interacted object (string), and the amount of time the user was interacting with the object (float).
- **3D objects translation and rotation (3D vectors):** Consists of 6 floats describing the position and rotation of an object, with which a hand has interacted.
- **Press button (event):** Some 3D objects provide an extra functionality while holding them, such as pressing the button for activating a drill.
- **Scenegraph traverse (event):** Information about traversing the scenegraph (e.g. go to next/previous action/stage/lesson).
- **Time (float):** The time that has passed since the start of the session, in seconds.

Figure 6 depicts the VR recorder pipeline, showing the different scripts that are involved as well as the files that are created. During replay, all “replay” avatars and interacted objects are recreated and referenced based on these recorded files. The replay functionality is handled by the **Replay** script.

### 4.3. The Basic Algorithms

In this section, the algorithms behind the four basic scripts involved in VRRR are presented.

**RecordingWriter** (see Algorithm 1) is responsible for writing all information regarding the position and the rotation of the logged objects, as well

as messages of events relevant to them. The `RecordingWriter` is implemented using the singleton pattern, i.e., only one script exists on each scene. Algorithm 1 provides the implementation of the `Recording Writer` script. In this algorithm, the `InteractionRecorder` script is added in the head and hands of all players when recording is started. The tracking objects, i.e., heads and hands, have two corresponding files where their transformations and messages relevant to them are stored. The `WriteToFile` public function is called by the `InteractionRecorder` and `PropagateRecording` scripts in order to write the information mentioned above. Finally, the `EndRecording` function closes all files when the session is finished.

---

**Algorithm 1** Recording Writer
 

---

```

1: Start();
2: for each player do
3:   Add Interaction Recorder Script in head and hands (tracking objects)
4:   for each tracking object do
5:     Create files for storing transforms and messages
6:   end for
7: end for

8: WriteToFile(tracking object, content, player):
9: Check whether content contains a message or a transform
10: if content contains message then
11:   Write content in messages file for the tracking object of player
12: else if content contains transform then
13:   Write content in transforms file for the tracking object of player
14: end if

15: EndRecording();
16: Close Transform and Message Files for each player

```

---

`InteractionRecorder` (see Algorithm 2), is responsible for capturing the transformations on each frame of the tracking object that this script is attached to, as well as all the events that are relevant. The `RecordingWriter` passes the ID of the player this game object is attached to, in order to send the corresponding information to the associated file. Afterwards, the type of the tracking object is found and, according to that, specific listeners are initialized. These listeners are responsible for sending messages to the `RecordingWriter` when specific events have been performed. Such kinds of events are interactions of hands with other objects or tools, or changes in the state of the scene, which are stored in the head's messages file. The `Update` function is responsible for sending the transformation of the tracking object to the `RecordingWriter`, and, also, check if an event has occurred in order to write it in the relevant file. Finally, the `OnBeginInteraction` and `OnEndInteraction` functions add or remove the `PropagateRecording` script to the game object the tracking object has started or finished interacting with, and, also, send a relevant message to the `RecordingWriter`.

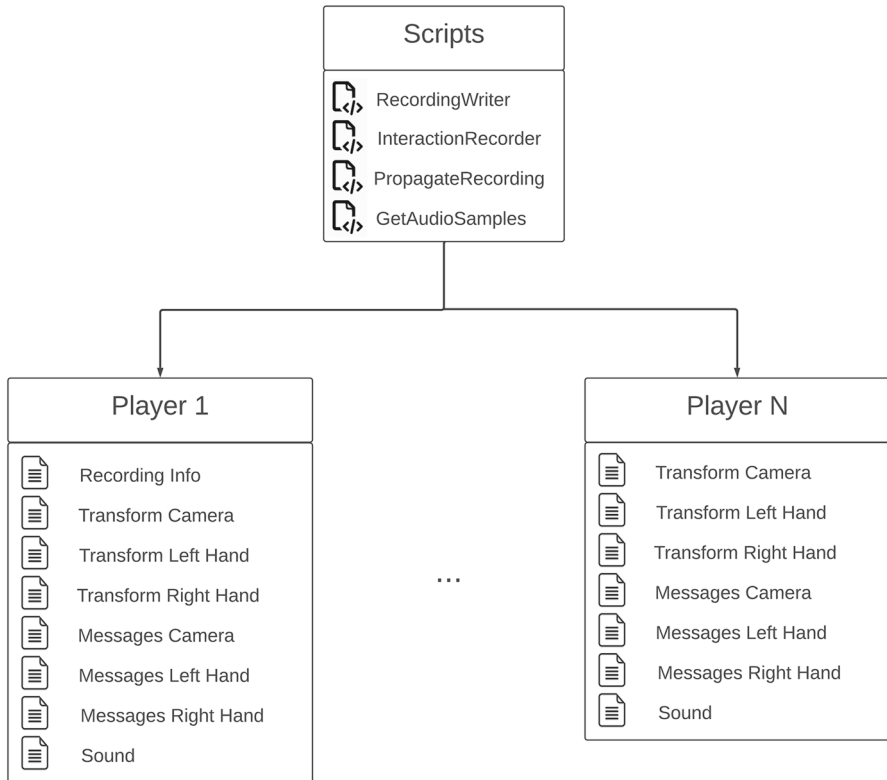


FIGURE 6. The associated scripts along with the generated files, in the context of recording a VR session of N players

**PropagateRecording** (see Algorithm 3) sends the transformations of all the game objects that the hands have interacted with to the **RecordingWriter**. At first, information about the player and the game object is stored. Then, a listener is added to that object, if it is a tool. This listener is responsible for adding the **PropagateRecording** script to the objects the tool has interacted with. Finally the **Update** function destroys the script, if the object has stopped moving, and, also, writes the transformation data using the player's ID and the object's name as parameters in order for the **RecordingWriter** to find the associated file.

Finally, **Replay** (see Algorithm 4) is utilized when a user chooses to watch a replay of a recorded session. This script is also a singleton, and all the other scripts access it by referring to its instance.

At start, all event actions are coupled with the associated messages which are either predefined, or have been added by the developer for a specific application. Thus, when **Replay** reads a message in the messages files, it knows which event to execute. For example, when the **Start Interaction** message is read, the algorithm calls the event that is triggered when an interaction of a hand with a game object has begun. This event executes the same commands

---

**Algorithm 2** Interaction Recorder

---

```

1: Player  $\leftarrow$  the ID of the player this gameobject refers to

2: Start():
3: if this gameobject is Hand then
4:   Tracking Object  $\leftarrow$  Hand
5: else if this gameobject is Head then
6:   Tracking Object  $\leftarrow$  Head
7: end if
8: if Tracking Object is Hand then
9:   Add listener OnBeginInteraction()
10:  Add listener OnEndInteraction()
11: else if Tracking Object is Head then
12:  Initialize Event Messages Functions
13: end if

14: Update():
15: Content  $\leftarrow$  Transform of this gameobject
16: RecordingWriter.WriteToFile(Tracking Object, Content, Player)
17: if Event has been executed then
18:   Content  $\leftarrow$  Event Message
19:   RecordingWriter.WriteToFile(Tracking Object, Content, Player)
20: end if

21: OnBeginInteraction(Interacted GameObject):
22: Add PropagateRecording script on Interacted Gameobject
23: Content  $\leftarrow$  Start Interaction Message
24: RecordingWriter.WriteToFile(Tracking Object, Content, Player)

25: OnEndInteraction(Interacted GameObject):
26: Remove PropagateRecording script from Interacted GameObject
27: Content  $\leftarrow$  End Interaction Message
28: RecordingWriter.WriteToFile(Tracking Object, Content, Player)

```

---

that are performed when users are in play mode. Therefore, the effect of the message is the same with having the avatar of a user perform a specific action. After the initialization of the event actions, the algorithm reads the information of the recording, such as if it is single-player or multiplayer. Afterwards, the wait time of each player is calculated, in order to synchronize all the players' avatars, because the users may have entered the session in different times. Also, this wait time is used for synchronizing the graphics with the sounds captured from the players' microphones. At last, the **Start** function opens all the transformation and messages files, in order to read their content on each frame on the **Update** function.

On each frame, the following commands are executed for each player. Firstly, waiting or skipping the graphics update is executed. This wait or skip

---

**Algorithm 3** Propagate Recording
 

---

```

1: Player  $\leftarrow$  the ID of the player this gameobject refers to
2: Tracking Object  $\leftarrow$  this Gameobject

3: Start():
4: if Gameobject is Tool then
5:   Add listener OnToolBeginInteraction on Interacted Gameobject
6: end if

7: OnToolBeginInteraction(Interacted Gameobject):
8: Add PropagateRecording script on Interacted Gameobject

9: Update():
10: if Gameobject is not moving then
11:   Destroy this script
12: end if
13: Content  $\leftarrow$  Transform of this Gameobject
14: RecordingWriter.WriteToFile(Tracking Object, Content, Player)

```

---

ensures that the graphics are synchronized with the sounds of each player's avatar. After that, the script reads the next line of the transformation and messages files and check if the sound and graphics are de-synchronized. Finally, a check whether an event has to be executed is performed. If there is an event for this frame, the message is executed. Otherwise, the transformation changes are applied to the hands, heads and game objects.

#### 4.4. VR Recording and Replay as Part of a Modern Game Engine

The VR recording and replay (VRRR) functionality introduced in this work is already implemented in the MAGES SDK [29, 31], developed by ORamaVR and available for public testing on ORamaVR's website [26]. A poster version of this work was recently accepted in SIGGRAPH [15]; a video summarizing this work can be found in [https://youtu.be/\\_aoEAOzlyPg](https://youtu.be/_aoEAOzlyPg). MAGES is a novel VR authoring SDK, scoping in accelerating the creation process of surgical training and the assessment of virtual scenarios. It is built on top of both the Unity3D and Unreal game engines and is composed of the following basic pillars:

- **Multiplayer:** collaborative networking layer that utilizes GA interpolation for bandwidth optimization.
- **Assessment:** real-time performer assessment both with supervised machine learning and predefined rule-based analytics.
- **Deformations:** GA-enabled deformable cutting and tearing, as well as configurable soft body simulations.
- **Curriculum:** tools for defining an educational curriculum enriched with visual guidance, gamified elements and objectives to enhance transfer of knowledge and skills.

**Algorithm 4** Replay

---

```

1: Start():
2: Initialize all Event Actions
3: Get recording information
4: for each Player do
5:   if Session is Multi-Player then
6:     Get Player's wait time
7:   end if
8:   Delay  $\leftarrow$  Player's wait time
9:   Start Player's Sound File with Delay
10:  Open Player's Transformation and Messages files
11: end for

12: Update():
13: for each Player do
14:   if Player Graphics have to wait then
15:     Wait graphics for Player
16:   end if
17:   if Player Graphics have to move forward then
18:     Skip graphics updates for Player
19:   end if
20:   Read Transform Files
21:   Check if Sound and Graphics are Desynchronized
22:   Read Message Files
23:   if Event has to be executed then
24:     Execute Message
25:   else if No Event to Execute then
26:     Apply Transforms on Hands, Head and Gameobjects
27:   end if
28: end for

```

---

- Prototyped surgical techniques: implementation of commonly used surgical techniques that can be customized in order to populate new content in a rapid manner.

The VRRR functionality extends the second and fourth pillars of the MAGES SDK, by enabling (a) experts to record their sessions, (b) novices to learn how to correctly perform an operation by watching the expert's recording and reviewing their own sessions, and (c) evaluators to assess the learning outcomes of the apprentices by evaluating the users via the use of VR replay (see Fig. 5).

Via VRRR, we may record and replay a VR medical operation, in both single player and multi player modes. These recordings can be synchronized with the cloud and also be replayed on any device regardless of the original hardware they were recorded on. This functionality is not just a video recording of the in-game view, but rather a full recreation of the operation as it happened when it was recorded. When replaying, the users are free to

move around the operation room and watch from any angle they like. The VR recorder allows to log the user's sessions within a virtual environment in the form of positions, rotations and interactions, resulting in improved accuracy without compromising generalization. Additionally, the accurate data recorded enable the playback feature. This feature can be applied for creating high fidelity VR replays that guide the trainee through his/her tasks.

## 5. Our Results

### 5.1. Metrics Regarding Transmission

The methods proposed in Sect. 3 were implemented in Unity3D and applied to a VR collaborative training scenario. Figure 1 illustrates an example of extreme hand-based interpolation in collaborative, networked virtual environments. In order to properly understand the significance of this figure, it is advised to watch the paper's presentation found in [17], where we demonstrate the effectiveness of our methods compared to the current state of the art. Specifically, we compare the three methods under different input rates per second, i.e., the keyframes sent per second to the VR rendering engine. The input rates tested are 5, 10, 15 and 20 frames per second (fps), where the last option is an optimal value to avoid CPU/GPU strain in collaborative VR scenarios. These rates are indicative values of the maximum possible fps that would be sent in a network whose bandwidth rates from very-limited (5 fps) to unrestricted (more than 20 fps). In lower fps, our methods yield jitter-less interpolated frames compared to the state-of-the-art method, which would require 30 fps to replicate similar output. As mentioned before, this reduction of required data that must be transferred per second by 33–58% (depending on the network quality, see Table 1) is multiplied by every active user, increasing the impact and the effectiveness of our methods in bandwidth-restricted environments.

The workflows of the two methods, compared with the current state of the art, are summarized in Fig. 3. In Fig. 7 we demonstrate the interpolation of the same object, at specific time intervals, for all methods; the intermediate frames feel natural for both methods proposed.

In Table 1, it is demonstrated that, under various network restrictions, both proposed methods required less data (in terms of updates per sec) to be transmitted via the network to achieve the same QoE. This decrease in data transfer leads to a lower energy consumption of the HMDs by 10% (on average, preliminary result) and therefore enhances the overall mobility of the devices relying on batteries. To measure this increase in battery life, we used various untethered VR HMDs (HTC Vive Focus 3, Meta Quest 2, Pico neo 3) where we run similar VR sessions with multiple (20+) users. In each session, we changed the transmission method and the updates interval rate as shown in Table 1, in order to maintain the same QoE. For each network quality level, we noted and compared the battery drain difference of the same HMD, after a fixed period of time, between the SoA method and our methods with the respective update setting. For example, in the “Excellent” tier, we compared the battery drain, after 20 min, of the same HMDs, running the



TABLE 1. Summary of the metrics of our methods (Ours) versus the state-of-the-art methods (SoA)

Network quality	How to achieve best QoE	Metrics on our methods
Excellent	SoA: 30 updates/s	33% less bandwidth
	Ours: 20 updates/s	16.5% lower running time
Good	SoA: 20 updates/s	50% less bandwidth
	Ours: 10 updates/s	16.5% lower running time
Mediocre	SoA: 15 updates/s	53% less bandwidth
	Ours: 7 updates/s	16.5% lower running time
Poor	SoA: 12 updates/s	58% less bandwidth
	Ours: 5 updates/s	16.5% lower running time

The first column describes the possible network quality which correlates to the maximum number of updates per second that can be performed. The second column contains the update rate required to obtain the same QoE under the specific network quality limitations. The third column contains the comparison of the bandwidth and the running time difference by our algorithms compared with the SoA algorithm, when using the respective update rates of the second column

SoA method with 30 updates/s against HMDs running the proposed methods with 20 updates/s.

Our methods provide a performance boost, decrease the required time to perform the same operation, with fewer keyframes but the same number of total generated frames, by 16.5% (on average). The running times were produced in a PC with a 3.1 GHz 16-Core Intel Core i9 processor, with 32 GBs of DDR4 memory. The same percentage of performance boost is expected in less powerful CPUs; in this case, the overall impact, in terms of absolute running time, will be even more significant.

## 5.2. Metrics Regarding VR Recording

An examination of the performance of the VR recorder was performed, and the impact on the computed frames per second (FPS) was assessed. For the evaluation, the frame rate (minimum, maximum and average) in two simulations was recorded, one with the VR recorder disabled and one with the functionality enabled; the results are reported in Table 4. In order to provide accurate results, similar events were triggered. From the obtained results, one can discern that only a minor, unnoticeable by the human eye, drop in FPS occurred by enabling the VR recorder, proof that the overall user experience was not affected negatively.

Since FPS is affected by constantly storing the translational and rotational data to files, we can further reduce the FPS load caused by the VR recorder by “skipping” data of several frames and instead generate them via interpolation, if later required. Such an approach will inevitably lead to severe reduction of the size of the stored data, depending on how many we skip. For example, if we choose to not record data on every other frame, we will

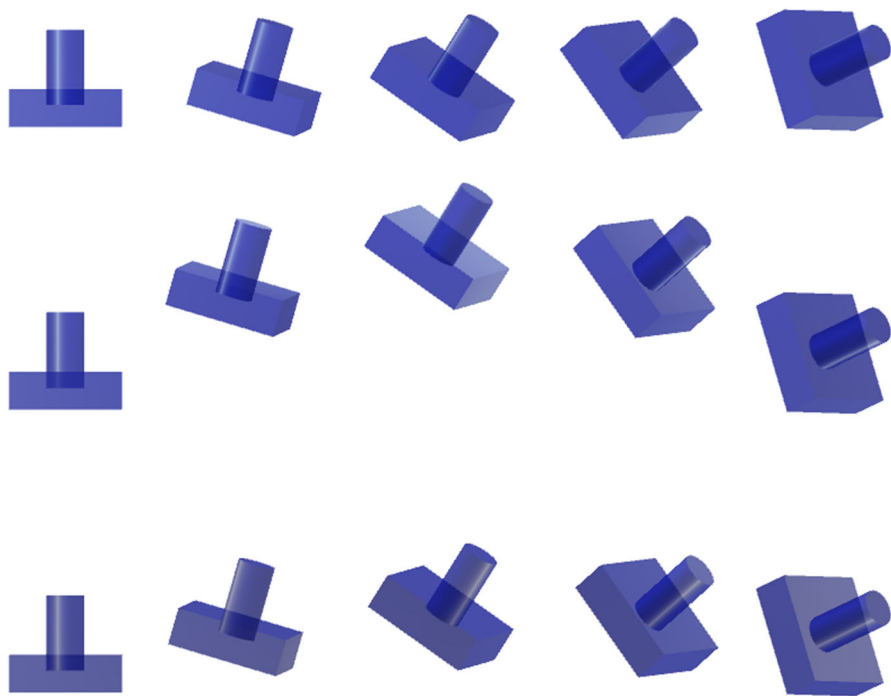


FIGURE 7. Different interpolation algorithms yield different, yet jitter-less, intermediate frames. (Top): state of the art: vector and quaternion separate interpolation. (Middle): dual-quaternion based interpolation algorithm. (Bottom): multivector based interpolation algorithm

TABLE 2. Mean relative errors of interpolated translations for 1-frame and 2-frame interpolation, using Euclidean norm

Algebra	1-frame error (%)	2-frame error (%)
Dual quaternions	0.02	0.009
Linear algebra	0.006	0.009
3D CGA	0.006	0.009

TABLE 3. Mean relative errors of interpolated rotations for 1-frame and 2-frame interpolation, using Euclidean norm

Algebra	1-frame error (%)	2-frame error (%)
Dual quaternions	0.02	0.02
Linear algebra	0.01	0.02
3D CGA	0.01	0.02

TABLE 4. Measuring the FPS burden of a VR application due to the recorder feature

Metric	Session without VR recording	Session with VR recording	Difference
Average FPS	89.56	85.13	4.43
Minimum FPS	76.56	68.78	7.78
Maximum FPS	93.29	92.57	0.72

Evaluation of the average, minimum and maximum FPS for a simulation with the functionality disabled (Column 2) or enabled (Column 3). These results were obtained by running simulations in a PC with an i7-11375H CPU, 16 GB of RAM and an RTX 3060 GPU

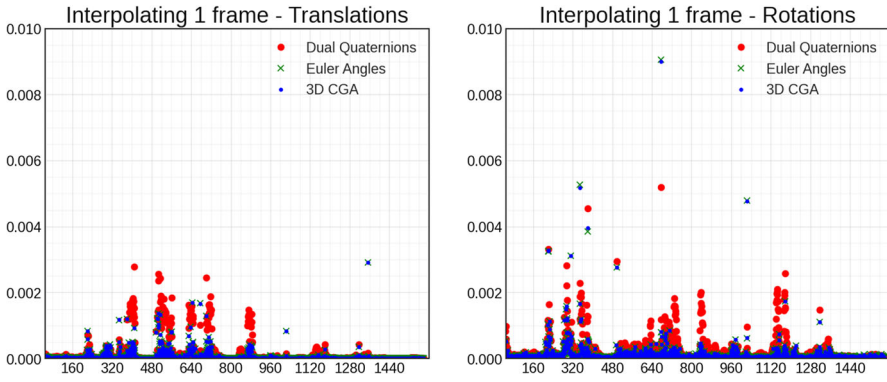


FIGURE 8. Results from Experiment A. The graph depicts the relative error (vertical axis) that occurs if we replace the translational (left) or the rotational data (right) of **one every two** frames by interpolated data. This interpolated data depends on the form used to represent the original displacement information; vectors and Euler angles (green cross), dual quaternions (red dots) or multivectors (blue dots). The horizontal axis refers the index of the frame for which the data are interpolated

have 50% lower size, whereas if we choose to keep data once per three frames we will need only 1/3 of the original storage space.

Of course, as we record less frames, we are susceptible to interpolation problems and artifacts may arise. Dealing with the interpolation of the stored data, in case of replaying, can be accomplished in the same way we dealt with the interpolation of the data transmitted over the network, in Sect. 3. As proven in that section, different representation forms for the same, stored, displacement data require different pipelines to be interpolated (see Fig. 3). Apparently, the results regarding the quality of the interpolated data depending on their form, presented in Sect. 5 and [17] also apply for the stored data.

To further demonstrate that using multivectors and/or dual quaternions to store positional and rotational data instead of the classic SoA forms, we performed two additional experiments. In both experiments, we recorded a VR session and stored the data both in SoA form, i.e., vectors for translation and Euler angles for rotation, as well as in multivector and dual-quaternion forms. In the first experiment (A), we deleted the data of every other frame whereas, in the second experiment (B), we kept the data of one every three frames. In this way, we emulated the data that we would obtain if indeed we recorded one every two or three frames respectively.

Depending on the representation form, we used the methods described in Sects. 3.4 and 3.3 to generate the “missing” data via interpolation ( $a = 1/2$  for experiment A and  $a = 1/3$  and  $2/3$  for experiment B). The data created in this way were then compared to the originally recorded data by performing the following steps. For every pair of data that we wanted to compare, we extracted the encapsulated translation vector  $(x, y, z)$  and the rotation vector containing the Euler angles  $(\theta_x, \theta_y, \theta_z)$ . Then, for each of these two vectors, we determined the relative error (using the Euclidean norm) between the original and the interpolated one.

Our findings are presented in Fig. 8 for the first experiment, and in Fig. 9 for the second one. In each experiment, we present the relative errors for the translational and rotational data separately. The results show that most displacement data have relative errors of less than **0.4** and **0.6%** for interpolating one frame and two frames, respectively. In Tables 2 and 3, we present the mean relative errors that regard the translational and rotational data respectively, for both experiments. These quantitative findings, along with the qualitative results of Sect. 5 and [17], prove that alternative, GA-based representation forms for displacement data are suitable for data recording as well data transmission over networks for multi-player VR sessions.

Of course, one could try similar experiments and keep, e.g., the data of one every  $n$  frames, for some random  $n$ . As  $n$  grows larger, we emulate the transmission of less “actual” data and the creation of more “artificial” interpolated frames. Inevitably, the results obtained, although they would remain quite similar in all methods, they would not qualitatively (e.g., when visualized) correspond to the actual movement of the object on the scene. For example, collisions or pass-through of objects in the scene would start to happen, or de-synchronization of objects that were supposed to move in a synchronous way could arise in such situations. The maximum  $n$  at which such phenomena start to appear depends strictly on the nature of VR-session and the “pace” of the recorded data, i.e., if user data corresponds to slow smooth movements, we can safely omit recording more data and still obtain close-to-the-original interpolated frames.

## 6. Conclusions and Future Work

This work suggests the use of two alternative representation forms, namely dual-quaternions and multivectors, to encapsulate the displacement information of the users in the context of a shared, collaborative virtual environment.

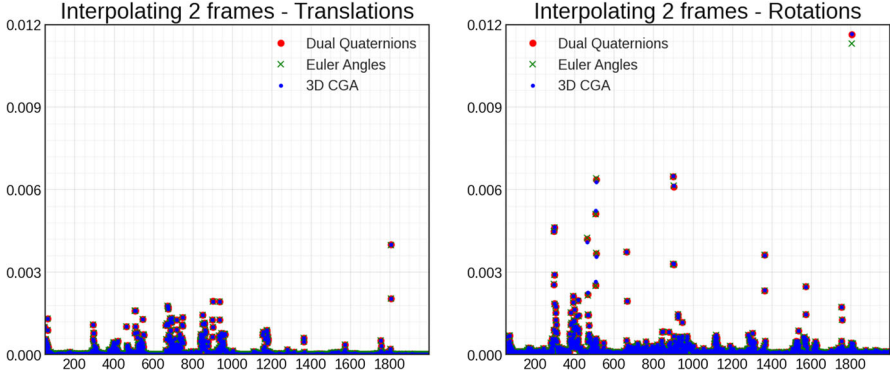


FIGURE 9. Results from Experiment B. The graph depicts the relative error (vertical axis) that occurs if we replace the transitional (left) or the rotational data (right) of **one every three** frames by interpolated data. This interpolated data depends on the form used to represent the original displacement information; vectors and Euler angles (green cross), dual quaternions (red dots) or multivectors (blue dots). The horizontal axis refers the index of the frame for which the data are interpolated

These forms, based on dual-quaternions and multivectors of 3D Projective or Conformal Geometric Algebra, require specific interpolation techniques that we present here. Crucially, we provide the way to transmute between these forms and the classic SoA representation, i.e., vectors and quaternions for translation and rotation. The benefits of using the proposed forms is demonstrated for two major VR functionalities; data transmission over the network and data recording.

Regarding data transmission over the network, we apply our proposed methods in a modern game engine and provide convincing evidence (see the video in [17]) that they outperform SoA methods, offering increased QoE, especially as the network quality, in terms of bandwidth, deteriorates.

Regarding data recording, we introduce a novel method that describes the functionality and characteristics of an efficient VR recorder with replay capabilities. Our proposed representation forms can be used to effectively store 3D scene transformation data. In the case that specific data is intentionally omitted to be recorded, for storage efficiency purposes, the use of the suggested interpolation methods will generate data “close” to the omitted, with insignificant relative error.

Regarding future work, the results of our proposed interpolation algorithms can be further improved by using optimized C# Geometric Algebra bindings to efficiently perform complex operations such as dual-quaternion or multivector SLERP. Moreover, by using the data logged with the VR recorder, we plan to create (a) an assessment tool that evaluates how the

users perform on the given tasks, (b) intelligent agents that are able to complete tasks on their own and (c) a no-code VR authoring tool, with which the environment designers can develop new training modules.

The assessment tool will be developed by training supervised learning algorithms with labelled action data, provided by the simulation designer. For example, the designer will provide multiple session data labelled from 0 to 10, depending on whether he/she performed the action poorly (0) or perfectly (10). The intelligent agents will be trained using such experts' session data and the no-code VR authoring tool will fuse all recorded data and train machine learning algorithms in order to understand what task the designer wants to develop. An initial step can be found in [2], where the authors have developed a Convolutional Neural Network (CNN) which is able to evaluate cuts in a surgical virtual environment. The transformation data (translations and rotations) of the cuts are fed to the neural network, and scores of the cuts, labelled by the surgical simulation designer, are the classes of the classification problem. In a future version, we plan to utilize dual quaternions and multivectors as the input form of the neural networks and examine whether data in such algebras can achieve better training results.

Also, inspired by the Quaternion Convolutional Neural Network (QCNN) [32, 37], we aspire to formulate and develop the Dual Quaternion Convolutional Neural Network (DQCNN) and the Multivector Convolutional Neural Network (MCNN). Lastly, QCNN algorithms can also be deployed to address the classification problem (similar to the one posed in [2]), especially when used for rotational data, while keeping CNN for translational data. We assume that the overall accuracy will increase, since the CNNs treat the transformation data as six unrelated features, while the QCNN processes the rotations as a hypercomplex number, and therefore takes into consideration their interrelationship information.

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**Data Availability** The datasets generated during and/or analysed during the current study are available from the corresponding author on reasonable request.

## Declarations

**Conflict of interest** All authors are members of ORamaVR SA, a spinoff startup company of Foundation of Research and Technology - Hellas, specializing in medical training via XR. Professor George Papagiannakis, Dr. Manos Kamarianakis as well as Lydatakis and Kentros are affiliated with

University of Crete. The authors have no competing interests to declare that are relevant to the content of this article.

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