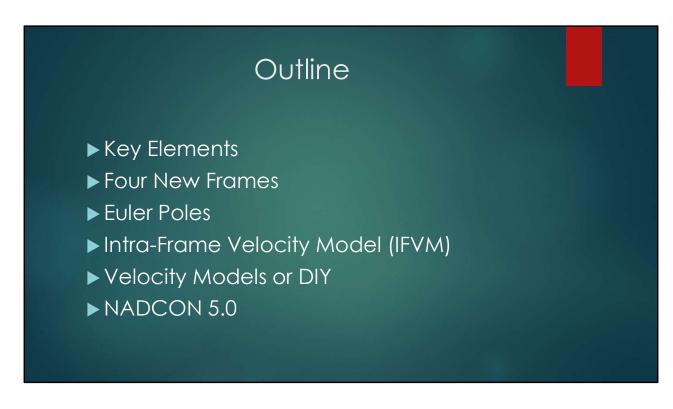


In 2022, the entire National Spatial Reference System (NSRS) will be modernized.

This class addresses the geometric aspects of the NSRS.

<CLICK>



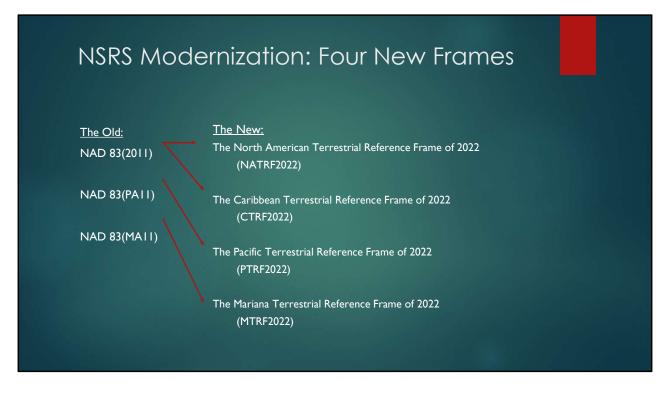
2022 is coming.

We will be discussing the Key Elements, The Reference Frames, the Euler poles, NEV or IFV, Velocity models, and NADCON 5.0.

<CLICK>

Key Elements

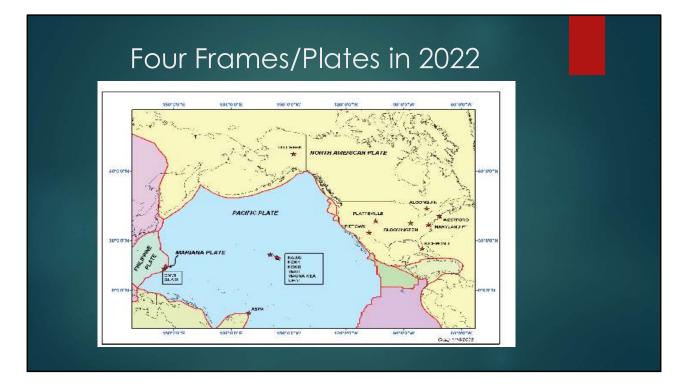
- ▶ Will be tied to most recent ITRF (2020?)
 - ▶ Epoch date TBD likely 2020.0
 - Four Frames: North America, Pacific, Caribbean, and Mariana
- > At epoch date, all frames identical to ITRF
- > Then each frame rotates about an Euler pole
- ▶ Velocity models describe motion in frame
- Access to the four frames via OPUS tool



The NSRS currently contains three reference frames (historically "horizontal datums"), known as NAD 83(2011), NAD 83(PA11) and NAD 83(MA11) which are used to define the geodetic latitudes, geodetic longitudes and ellipsoid heights of all points in the USA.

These three frames will be replaced with four new reference frames, called:

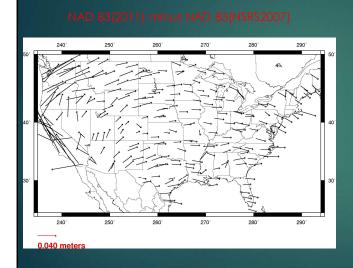
North American Terrestrial Reference Frame of 2022 (NATRF2022) Pacific Terrestrial Reference Frame of 2022 (PTRF2022) *Caribbean Terrestrial Reference Frame of 2022 (CTRF2022)* Mariana Terrestrial Reference Frame of 2022 (MTRF2022)



Replacing the NAD 83's

- <u>Three</u> plate-(pseudo) fixed frames will be replaced with <u>four</u> plate-fixed reference frames
 - N. Amer., Pacific, Mariana, Caribbean(new!)
- Remove long-standing non-geocentricity of NAD 83 frames
- All four : identical to ITRFxx at a TBD epoch
 2020.00?
- All four : differ from ITRFxx by plate rotation only
 - ► Updated Euler Pole determination for rigid plate only

Plate-(pseudo)fixed frames



NAD 83(NSRS2007)

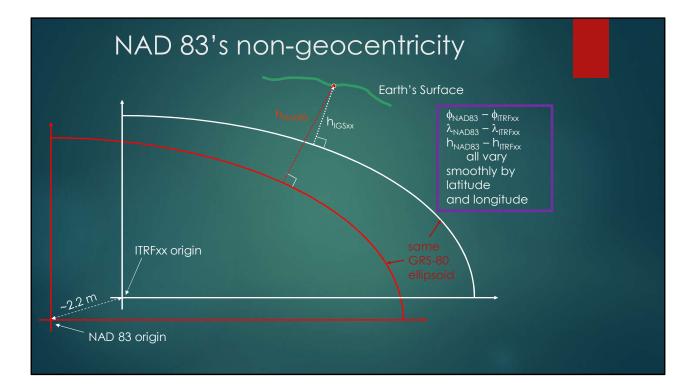
NAD 83(2011)

If NAD 83 were truly "plate fixed"

then <u>an 8 year epoch change</u> would not yield the systematic plate rotation seen here.

(*)TRF2022 will determine a new Euler Pole rotation for each of the 4 plates.

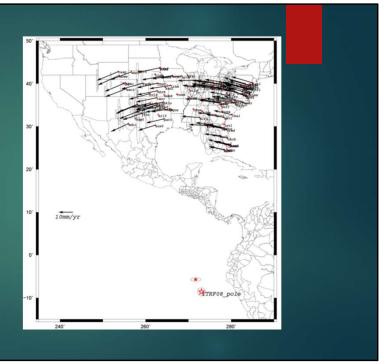
(*)=NA, C, T or P

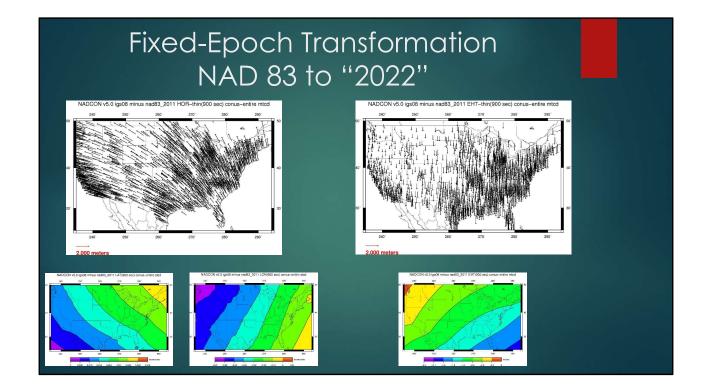


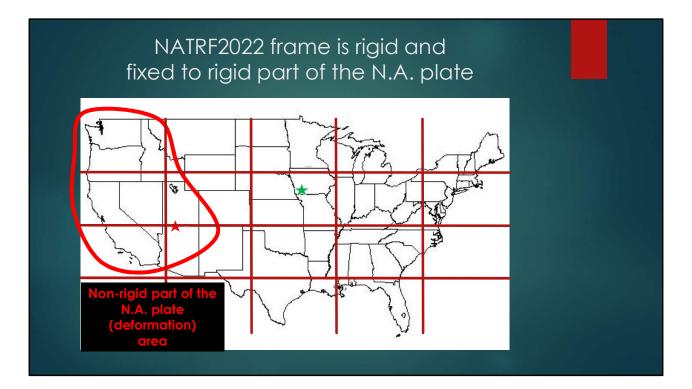
Each frame will get 3 parameters

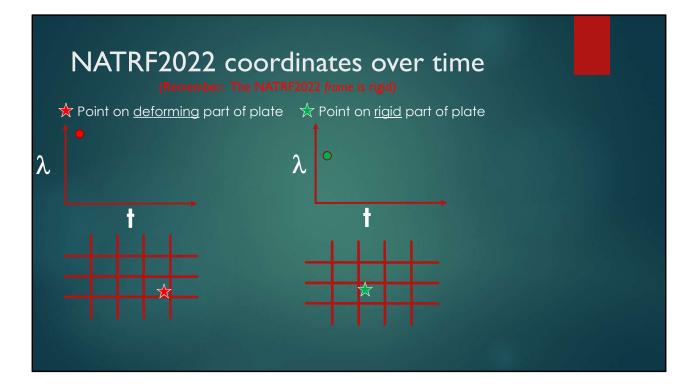
- Euler Pole Latitud
- Euler Pole Longitude
- Rotation rate (rad/yr)

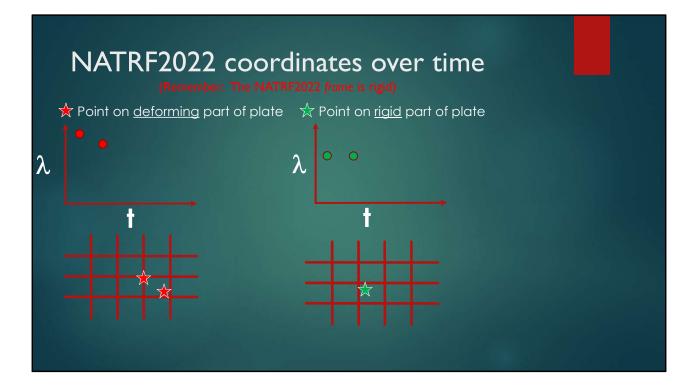
Used to compute time-dependent TRF2022 coordinates from time-dependent ITRF coordinates.

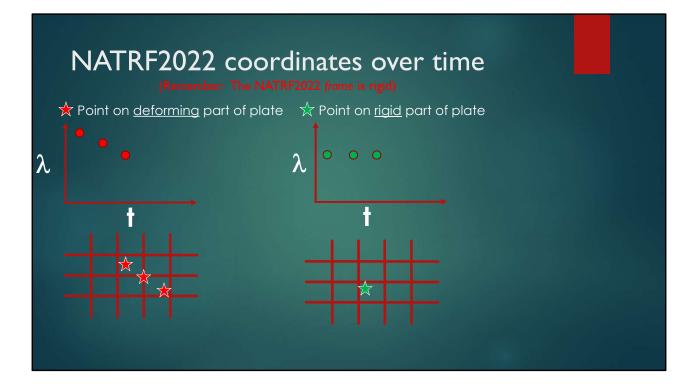


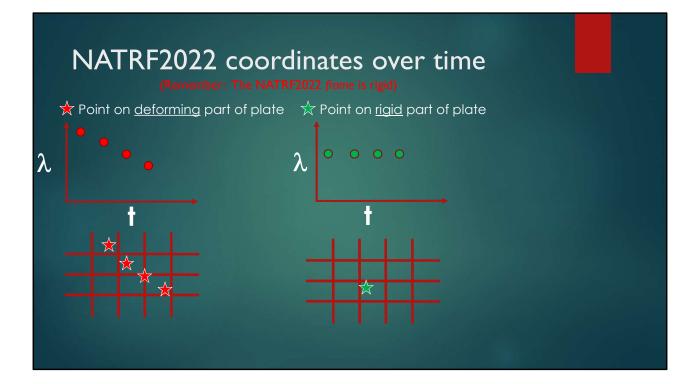








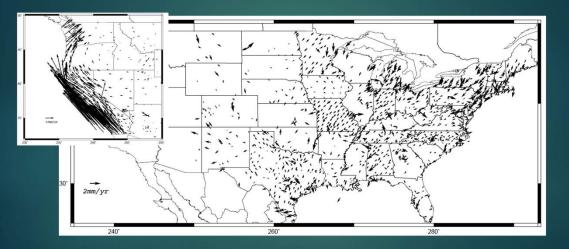




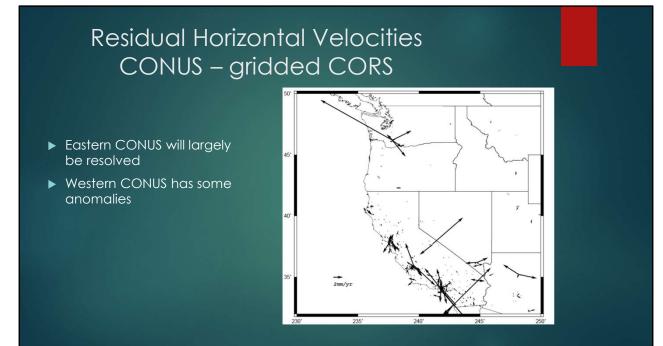
NEV or IFV

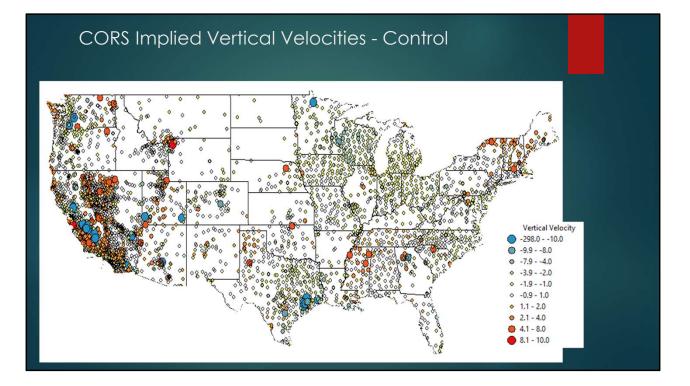
- Euler poles mostly account for horizontal vel.
 - Remaining signal currently modeled by HTDP
 - ▶ HTDP complicated to maintain and only horizontal
- ▶ So if not HTDP, then what?
 - A TBD velocity model needed for horizontal and vertical motions (e.g. 3D)
 - ▶ Non-Eulerian Velocity (NEV) vs. Intra-Frame Velocity (IFV)
- Simplest solution is to grid CORS velocities

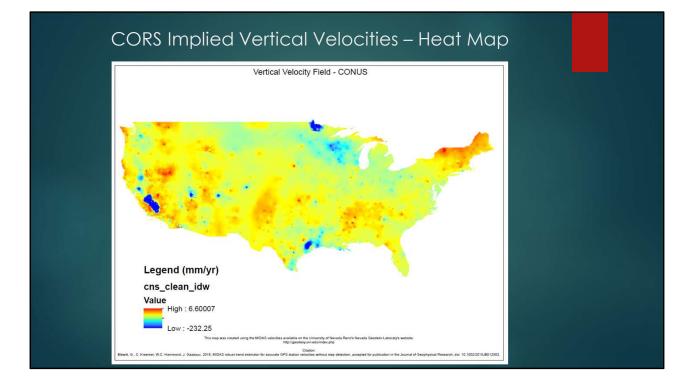
Horizontal velocities after Repro1



Note scale difference between West (10 mm/yr) and east (2 mm/yr)

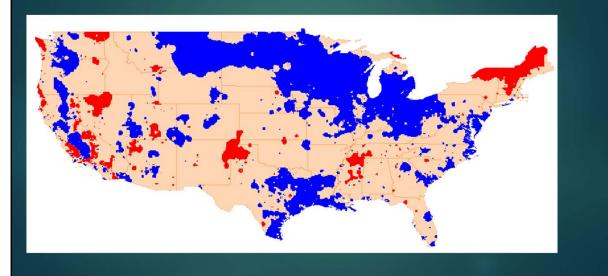


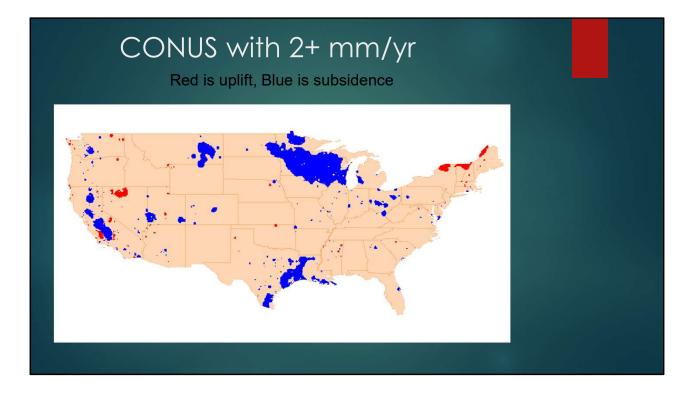


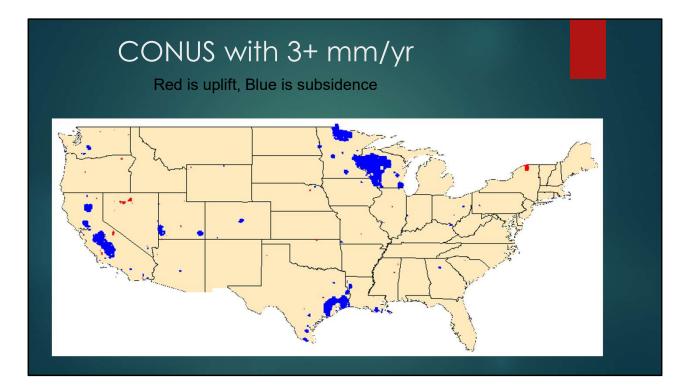


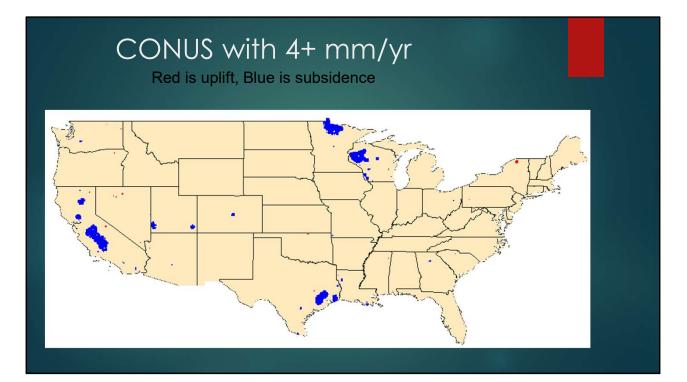
CONUS with 1+ mm/yr

Red is uplift, Blue is subsidence

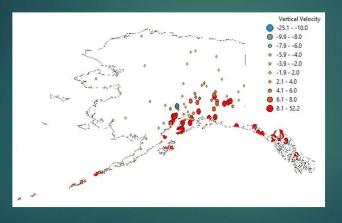


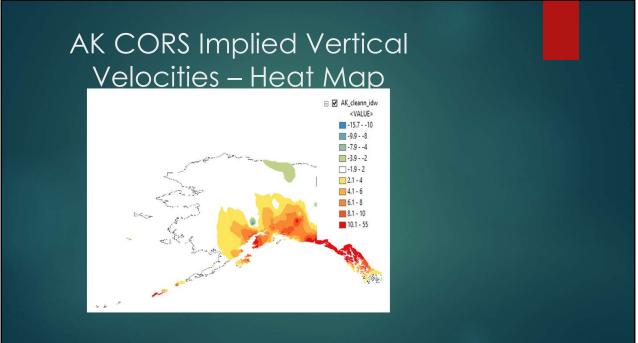






AK CORS Implied Vertical Velocities – Control



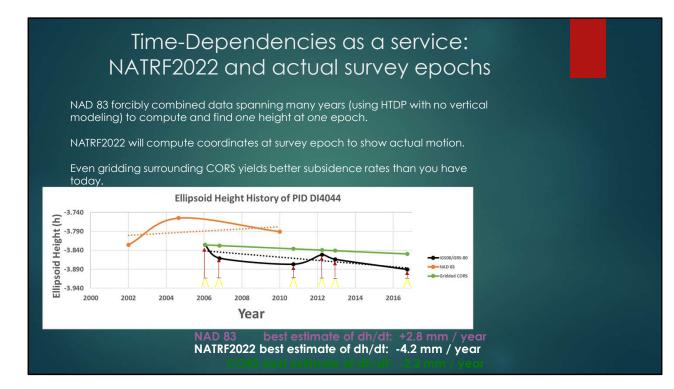


How to use this information?

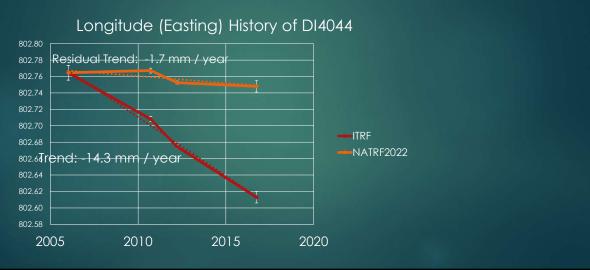
- Assuming CORS spacing is sufficient grid
 - > Yields horizontal (NEV & GIA) plus vertical signal
- Vertical important for orthometric heights:
 - $H^{\dagger} = (h^{\dagger 0} + (t t_0)^* dh/dt) (N^{\dagger 0} + (t t_0)^* dN/dt)$
 - ▶ Where H^t is orthometric height at desired time
 - ▶ h^{t0} is ellipsoidal height at epoch (maybe 2020.0)
 - ▶ N^{t0} is geoid height at epoch
 - ▶ dh/dt is change in ellipsoid height over time
 - dN/dt is change in geoid height over time (GeMS)

Velocity Models or DIY

- ▶ We will investigate sufficiency of gridded CORS
- Concern is dynamic areas: horizontal & vertical
 - ▶ Will gridded CORS work in Alaska?
 - ▶ What if this isn't enough?
- Will look at other models to evaluate
- Cost benefit
 - ▶ What we can easily do in-house and support
 - increased complexity from outside models
- ▶ Alternatively, users can model their own ...



Time Dependencies as a service: Intra-plate motions



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