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A Spatio-Semantic Approach to Reasoning about Agricultural Processes

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Abstract Digitization of agricultural processes is advancing fast as telemetry data from the involved machines becomes more and more available. Current approaches commonly have a machine-centric view that does not account for machine-machine or machine-environment relations. In this paper we demonstrate how to model such relations in the generic semantic mapping framework SEMAP. We describe how SEMAP's core ontology is extended to represent knowledge about the involved machines and facilities in a typical agricultural domain. In the framework we combine different information layers – semantically annotated spatial data, semantic background knowledge and incoming sensor data – to derive qualitative spatial facts and continuously track them to generate process states and events about the ongoing logistic process of a harvesting campaign, which adds to an increased process understanding.

Keywords semantic mapping, environment modeling, ontologies, agriculture

1 Introduction

Digitization of agricultural processes currently concentrates on recording and processing telemetry data from individual machines to support precision farming. This implicitly leads to a machine-centric view on the ongoing processes. But many agricultural processes are complex, cooperative orchestrations of multiple machines. Automatic decision support in harvesting campaigns is still limited in

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assistance systems, as representations of cooperative agricultural processes and tools to analyze inter-machine relations are mostly missing.

Information on the whole process can not be derived from a single machine's telemetry data, but is covert in the combined telemetry of multiple machines. To embed this abstract data from different machines in the context of the ongoing process, machine data has to be fused with additional knowledge and information about the environment and the process itself. Most importantly, symbolic representations of the spatial relations between agricultural machines and their environment are needed to identify and monitor process states and associated events. Analyzing the geo location of individual machines and processing of spatial relations between them is therefore a valuable contribution to automated process managing in agriculture. Modern agricultural machines already provide a geo-referenced stream of telemetry data, based on RTK-GPS. The positional data is often used to inspect the containment of machines in polygonal boundaries representing fields and farms, to spatially locate machines at those facilities. Such a quantitative, geometric analysis already extracts a lot of relevant information, but does not account for qualitative relations between the machines and facilities nor for knowledge representation and reasoning on a semantic level.

Representing such spatial relations in terms of a well-defined semantic terminology allows to infer complex facts, built up from basic spatial relations to take a process-centric view on harvesting campaigns. This requires a machine-readable environment model that can be paired with geo-referenced telemetry-data from agricultural machines to geo-localize individual machines and derive spatial relations between machines and their environment, respectively. To meet these requirements, we use the semantic mapping framework SEMAP [6] to represent an agricultural domain. We show how to create a semantic environment model for agricultural environments and machines and how to connect it to the underlying geometric model. We illustrate how to ground qualitative spatial relations between a static environment and a set of dynamic vehicles with SEMAP. We further extended this ontological model which represent the activities and events of a harvesting operation, to enable an event-based tracing of the process.

In an application example, we replay telemetry of a harvesting campaign to continuously update the spatio-semantic environment model to derive symbolic facts about the ongoing process. Via rule-based inference we analyze the domain-specific spatial relations of a maize harvesting campaign to detect events such as the correct positioning of a transport vehicle next to the harvester for overloading.

2 Related Work

State of the art solutions in digital agriculture allow to record and process telemetry data of agricultural machines like position, velocity, and internal parameters like fuel consumption or mass throughput [16]. This data is used in precision farming to optimize the application of fertilizers or herbicides, and collected in farm management information systems to aggregate telemetry data to analyze the performance of agricultural machines [14]. They also help to plan agricultural operations by maintaining information about crop rotations [7] or by creating field boundaries and sub-plots based on GPS data [11] to support the application of fertilizers and herbicides tillage strategies [15]. Automated scheduling of entire harvesting campaigns is also possible [1]. Usually, these solutions operate on centralized systems with web-based front ends [9]. This often causes severe latencies due to connectivity issues in remote or rural areas [12].

Fleet overview applications inform the operators about an on-going harvest operation by exchanging telemetry information between machines in real time and display vehicle positions on a static 2D map. Process-related decision making is still completely in the operator's hands, as these assistance systems do not provide a context-dependent and process-oriented analysis. To automatically detect relevant situations that give insight into the agricultural process – e.g., an empty transport vehicle arriving at the field ready for overloading – is a key feature to increase process transparency, which is necessary for improving agricultural efficiency through more process-oriented decision support systems.

To solve these problems, existing approaches from semantic mapping in robotics can be transferred to this application domain. Semantic maps are representations that in addition to spatial data provide assignments to known concepts for the mapped entities, such that semantic background knowledge can be used to reason about the environment [13]. Recent advances in semantic mapping are concerned with constructing general models of multi-modal environment data that can be flexibly queried for task-specific data in individual applications, see [10] for an overview.

Being able to analyze spatial relations in terms of qualitative predicates is important in data retrieval and reasoning. To fully utilize qualitative spatial reasoning, it is necessary to derive qualitative symbolic data from quantitative metric information. In [17], Wolter and Wallgrün pointed out that this process of qualification is essential for qualitative spatial reasoning in practical applications, but still rarely seen. The lack of qualification is also apparent when working with semantic maps. Tools for performing spatial analysis on quantitative metric data are also seldom used in semantic mapping. In our previous work [6], we showed the advantages of maintaining environment data in form of a generalized and persistent model, from which task-specific semantic maps can be extracted, rather than maintaining and aligning several different layers of semantic, geometric and topological information in parallel. We proposed to pair spatial databases and declarative knowledge bases to combine ontological and logical rule-based inference with spatial querying and analysis capabilities and called it the semantic mapping framework SEMAP.

In this paper, we integrate an ontology for agricultural processes into SEMAP to make knowledge about harvesting campaigns accessible for automatic analysis. We use this knowledge together with SEMAP's spatial reasoning capabilities to recognize relevant events in an maize harvesting process. In the presented experiment we were able to detect the correct positioning of an overloading vehicle based on recorded telemetry in an real life harvesting campaign.

3 The SEMAP Framework

The SEMAP framework is designed to represent and manage spatio-semantic environment data. Its purpose is to provide information about the objects and the environment in a specific application domain. It connects conceptual knowledge about the environment and factual knowledge about present object instances with

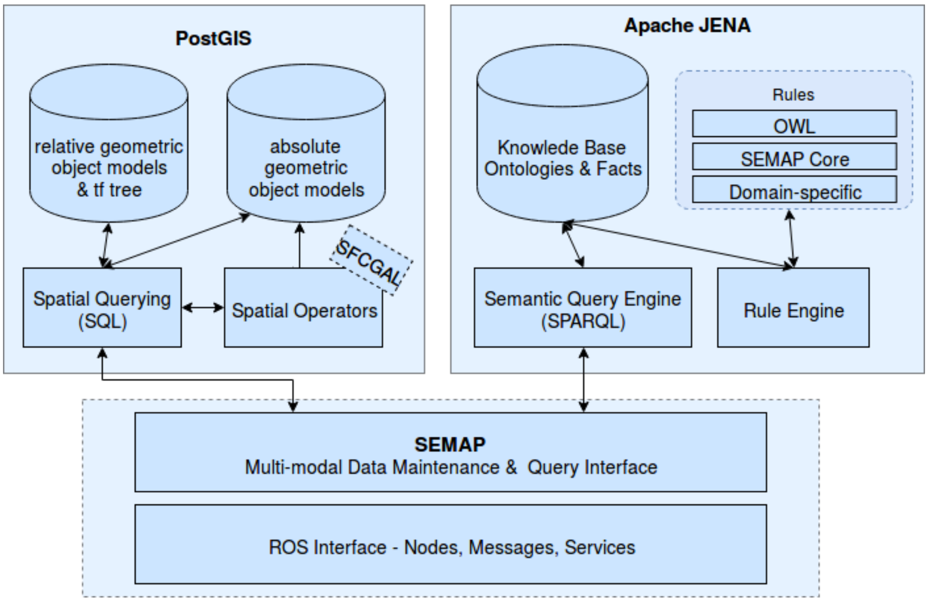


Fig. 1: SEMAP's architecture features a spatial database and a knowledge base system, which are combined by a multi-modal querying interface.

their geometric representations to hold a combined spatio-semantic model that allows spatial analysis as well as semantic inference. To manage the fundamentally different structure of semantic and spatial information, SEMAP internally separates environment data into two dedicated databases to ensure optimized performance for each data modality especially in terms of data storage and retrieval. An outline of SEMAP's internal structure is given in Fig 1. The semantic part is represented by a knowledge base system component (KB) that is based on description logics with the obligatory separation into terminological and asserted knowledge. The environment's conceptual model and facts about the environment are represented in the Web Ontology Language (OWL) [3] and maintained in Apache JENA, which provides inference for ontological and rule-based reasoning as well as the capability to query the stored knowledge. The spatial part is a dedicated spatial database system (DB) that stores geometric primitives, and provides operators for quantitative spatial analysis and spatial querying. It is implemented as an extension to PostGIS using the SFCGAL plugin to create custom spatial operators, especially for detecting 3D spatial relations.

The framework's strength lies in combining both query systems to support combined queries with semantic and spatial aspects. In such queries, SEMAP utilizes the DB's spatial operators to ground qualitative spatial relations that are only stored implicitly in the geometric environment representation. Such relations are automatically inserted into the KB as facts for further inference. This approach enables rule-based reasoning and to construct complex spatial queries based on simpler deductions. This multi-modal query interface is advantageous in real-world applications, as it allows to answer complex questions about the positions, relations and roles of the stored objects in a natural way. The framework's core components are designed to be domain-independent, yet extensible with domain-specific semantic models, rule-sets and geometries. A more detailed description of the SEMAP framework and its spatial querying capabilities is given in [6].

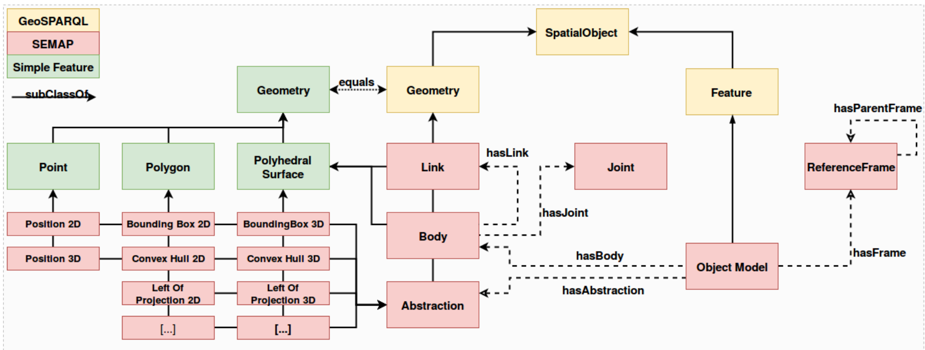


Fig. 2: An excerpt of the ontology that implements the semantics of SEMAP's environment model.

Fig. 2 sketches SEMAP's core ontology. It uses standards from the Open Geospatial Consortium (OGC), because these well-defined models of geo-spatial data are in alignment with PostGIS's data types, which were also defined by the OGC. GeoSPARQL's `SpatialObject` and the fundamental distinction between geometries and features are integrated in SEMAP's upper ontology.

Here, the concept `Geometry` describes any kind of spatial primitive and provides a semantic wrapper for all OGC data types and serves as a bridge to the well known Simple Feature Ontology. SEMAP's KB contains a corresponding `Geometry` sub-concept, for every geometric primitives stored in SEMAP's DB. The property `semap:hasDbId` is used to create an associative link between the geometric primitive and its semantic wrapper. SEMAP internally uses these associations to join spatial and semantic data.

The super-concept `Feature` is used for all things that can be described spatially like SEMAP's `ObjectModel`, which aggregates sets of semantically wrapped geometries to represent an object. For this, it uses the `geo:hasGeometry` property and its two specializations: `semap:hasBody` composes a set of geometries that constitute the object's actual body. In case of articulated objects, the `Link` and `Joint` concepts are used to describe the object's kinematics. `semap:hasAbstraction` provides a set of coarser representations, like oriented and axis-aligned bounding boxes and convex hulls. These abstractions are used for accelerated spatial processing and enable the analysis of directional relations like `left-of` or `above-of`, based on projection and half space geometries described in [4].

To create a spatio-semantic environment model for a particular application, domain-specific ontologies, knowledge bases and rule-sets can be imported into SEMAP. To describe domain-specific concepts spatially and reason about them as part of SEMAP's environment model, the respective entities can be associated with an `ObjectModel` via the `semap:hasObjectModel` relation, cf. Fig. 5 (b).

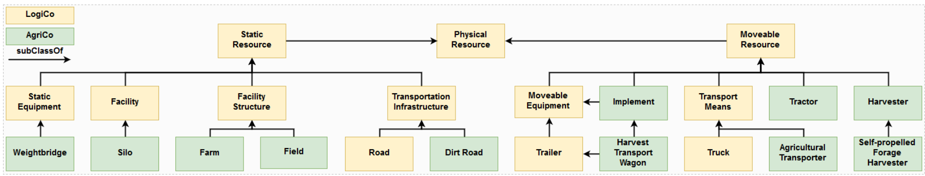


Fig. 3: Excerpts of the domain-specific model added to SEMAP. The LogiCo ontology (yellow) provides a model of static and movable resources, to which the AgriCo ontology (green) adds agricultural concepts like farms and tractors.

4 Applying SEMAP in Agriculture

In this section, we detail the process of customizing SEMAP for a specific application domain. Our goal is to create a spatio-semantic model of agricultural environments and machinery in SEMAP for spatial analysis and rule-based reasoning to derive more information about ongoing agricultural processes that involve multiple machines.

First, we present the description of the semantic model used to represent agricultural concepts, such as fields, farms and tractors in SEMAP's knowledge base. After that we discuss how spatial data is added to this ontological model and how telemetry data recorded from actual agricultural machines can be used to continuously update the constructed environment model. Next, we demonstrate how to use SEMAP for grounding basic spatial predicates between agricultural machines and their environment and how rule-based reasoning is used to identify complex and domain-specific spatial relations. Finally, we present an ontological model for describing agricultural processes in terms of their activities and related events and illustrate how SEMAP's capabilities to answer both spatial and semantic queries, can be used to effectively instantiate the proposed process model to gain more insight into an ongoing agricultural process.

Throughout this discussion, the chosen application example is concerned with the detection of relevant states and events during a maize harvesting campaign, especially the spatial relations between transport vehicle and forage harvester while overloading crops.

4.1 The AgriCo Ontology

Our semantic model for describing agricultural machinery and their environments is based on the logistics core ontology (LogiCo) by Daniele et al. [5]. This semantic model describes environments and resources in logistics. Since this domain is very similar to the general process of harvesting, we extended LogiCo with additional concepts needed to represent agricultural processes. We call this extended ontology AgriCo as depicted in Fig. 3.

All components of our model are based on `Physical Resources` in the real world, which can be `Static` or `Movable Resources`. Three sub-classes are used to describe static locations of interest: The `Facility` concept defines areas and structures designated for a specific purpose in the given domain and the `Facility`

```
?tractor rdf:type agrico:Tractor
?trailer rdf:type logico:Trailer
?tractor agrico:hasImplement ?trailer
==>
?tractor rdf:type agrico:AgriculturalTransporter
```

Fig. 4: A rule to detect agricultural transport vehicle.

`Structure` defines aggregates of different facilities. In AgriCo, for example, `Farm` serves as an aggregate of agricultural facilities like `Silos`. Additionally, the `Static Equipment` concept describes utilities available at a facility, e.g., a `Weightbridge` for weighing transport vehicles. Another important sub-class of static resources are the different kinds of `Transportation Infrastructure` to represent connections between locations. Since this important concept was missing in the LogiCo ontology, we added this concept and suitable sub-classes like `Roads` and `Dirt Roads`.

For movable resources, LogiCo gives concepts for `Transport Means`, i.e., trucks, and `Movable Equipment` such as trailers. Since `Tractors` can not transport goods without an appropriate attachment, AgriCo provides the basic concept `Tractor` as a direct sub-class of movable resource and additionally the `Implement` concept as a specification of movable equipment. It serves as super-concept for the various kinds of machinery that can be connected to a tractor, e.g, plows, sowers. The `hasImplement` relation is used to express that an instance of an implement (or trailer) is attached to an instance of tractor. To describe machinery configurations suitable for agricultural transport activities, AgriCo defines the generic `Agricultural Transporter` concept. Instances of this concept need to be asserted or derived, i.e.,. by the rule shown in Fig. 4.

Based on these concepts it also possible describe very specific agricultural resources such as `Harvest Transport Wagons`, which inherit properties from the trailer and implement concept simultaneously. In this way, we can denote the trailer's volumetric capacity via the `logico:hasCapacity` attribute, as well as the interfaces use to control the active pickup systems and scraper floor via the `agrico:hasISOBUSInterface` relation.

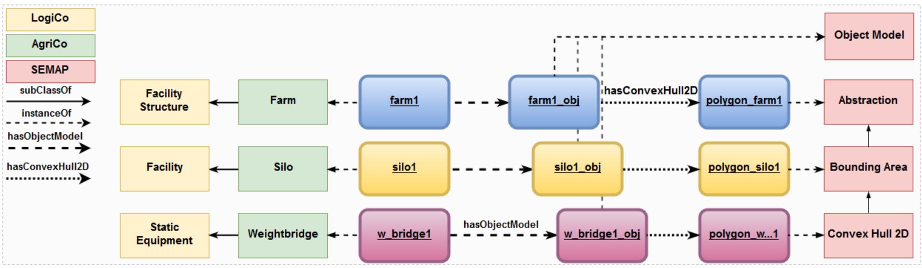
Finally, the `Harvester` concept is used to represent combine and forage harvesters, which are directly derived from the `Movable Resource` concept, too, as they can not be used for transporting goods in a supply chain.

4.2 Instantiating the Environment and Machinery Model

The semantic model presented so far provides the conceptual basis from which instances of agricultural facilities and machinery can be created and described. To link them to a spatio-semantic data set in SEMAP, we proceeded as follows:

First, we imported the AgriCo ontology into SEMAP's KB component. Next, we allowed that the `hasObjectModel` property can map from instances of LogiCo's `Physical Resource` to SEMAP's `ObjectModels`. This way, the domain-specific concepts and instances thereof can have a spatial representation in SEMAP. Finally, we instantiated the agricultural concepts and their spatio-semantic representation with an appropriate data set.

(a) The spatial data used to represent a farm (incl. silos) and two fields.



(b) The semantic representation within SEMAP's knowledge base.

Fig. 5: To represent a farm's facilities in SEMAP, we used the 2D polygonal boundaries, shown in (a), stored in the DB component. These spatial model are connected to instances of the domain-specific concepts of AgriCo via SEMAP's `ObjectModel` concept, as illustrated in (b).

To setup static resources in our environment model, we used a set of polygonal boundaries to represent farms and fields and other facilities. Fig. 5 (a) shows an excerpt of the environment. It consists of the farm's grounds (blue), three silos (orange) and a vehicle scale (violet), as well as two fields (green). The data was modeled in Google Earth and automatically read into SEMAP's KB and DB components using a KML file importer. In Fig. 5 (b), the underlying semantic representation is depicted with three instances of AgriCo concepts related to their object representation using the **`hasObjectModel`** relation. Here **`farm1`** connects to **`farm1_obj`**. The polygonal boundary **`farm1_boundary`** is connected via the **`hasConvexHull2D`** property, which is a sub-property of **`hasAbstraction`**.

To add movable resources to the static environment, we created three dimensional and articulated object models of a tractor-trailer combination and a forage harvester as displayed in Fig. 7 (b). These objects are modeled in the Unified Robot Description Format, since SEMAP supports this format natively. The underlying semantic representation is a straight forward extension to the example in Fig. 5 (b), yet more complex due to the individual links and joints.

To introduce movement to our spatio-semantic model of farms and fields, we used telemetry data recorded on real agricultural machines to continuously update the position and articulation of the machines within it. We replayed the machines GPS signals and joint states in the Robot Operating System (ROS) and connected a bridge node to SEMAP, such that the environment model was updated accordingly.

4.3 Analyzing Spatial Relations

By moving the agricultural machines through the static environment in our experimental setup, the spatial relations between environment and machines and the machines themselves are changed continuously. SEMAP's spatial and semantic reasoning capabilities can be used to detect these spatial relations using geometric analysis and express them in terms of semantic spatial predicates.

SEMAP provides spatial operators to test for containment and intersection in 2D and 3D, as well as operators to identify directional relations, i.e.,. left-of, right-of. The same holds for distance-based relations, such as near-by or far-away, which can be parameterized to set a desired distance threshold. For a full discussion on SEMAP's spatial operators, see [6].

To use theses operators for reasoning about spatial relations between machines and their environment, we follow a two step procedure:

First, we make use of SEMAP's qualification capabilities to geometrically ground the spatial relation of interest by posing a suitable query to SEMAP's DB backend via its ROS interface. Fig. 6 (a) gives an example on how to test for containment between pairs of SEMAP's object models. The query identifies objects of type `Facility` as reference and those of type `MovableResource` as the targets. The query is further parametrized to uses the movable resource's 2D position for the geometric evaluation against the 2D convex hull of the facilities. Hence the given query performs quantitative spatial analysis, between the agricultural machines in our model and the surrounding environment by checking whether a machine's 2D position is spatially in a facility's boundary. The results of this query are then inserted into SEMAP's knowledge base as qualitative semantic knowledge about the spatial relations. In case of our example, the objects pairs found by the query are inserted as facts over the `semap:isIn2D` relation. Likewise SEMAP's ontological model defines relations such as `semap:leftOf2D` or `semap:containedIn3D`, which are extracted by the same query process.

Secondly, we use the derived spatial knowledge in order to reason about our agricultural application domain. For example, we can infer that for all pairs of machinery and environment entities for that the spatial predicate `semap:isIn2D` holds, the topological relation `logico:isAt` – which is defined in our domain ontology – holds, too. An example for such rule-based inference is given in Fig. 6 (b). Here, the rule identifies to topological location of a movable resource (i.e., a tractor) based on the spatial relation to any of the facilities contained in our model (i.e., fields and farms). While this seems a simple transition, it is important to note that this rule infers from a *spatial* predicate to a *topological* relation and that this assertion is grounded in the quantitative *geometric* data within SEMAP's DB. The rule is generic for all instances of `Movable Resource` at any instance of `Facility` and its sub-concepts, which makes it applicable in a wide range of applications.

```
rosservice call /containment_query
   "reference_object_types: ['Facility'] reference_object_geometry_type: 'ConvexHull2D'
    target_object_types: ['MovableResource'] target_object_geometry_type: 'Position2D'
    fully_within: false insert_kb: true"
```

(a) SEMAP query to extract containment relations.

```
?machine rdf:type logico:MovableResource
?machine semap:hasObjectModel ?machine_obj
?machine_obj semap:hasPosition2D ?machine_abstr_pos2D
?facility rdf:type logico:Facility
?facility semap:hasObjectModel ?facility_obj
?facility_obj semap:hasConvexHull2D ?facility_abstr_ch2D
?machine_abstr_pos2D semap:isIn2D ?facility_abstr_ch2D
==>
?machine logico:isAt ?facility
```

(b) Rule to ground topological relations based on spatial relations.

Fig. 6: To geometrically ground spatial containment relations, we used the query shown in (a). The query results where extracted into SEMAP's KB as facts over the `semap:isIn2D` relation and then used the rule (b) to derive that the topological relation `logico:isAt` holds between machines and facilities.

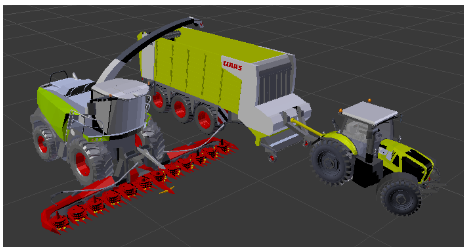
The underlying spatial querying is done automatically in SEMAP's multi-modal query interfaces, such that further queries to the environment model can be posed using the high-level relation `isAt`, without having to deal with the data transfer from DB to KB explicitly.

It is also important to note that the transition from spatial to topological information is explicitly coded through the shown inference rule. It is thus a matter of application design, how to implement this transition. Instead of using 2D containment, we could have also opted for grounding topological relations using a 3D spatial containment relationship or work with distance-based constraints.

It is this flexible approach in spatio-semantic reasoning that makes SEMAP beneficial when extracting information about a given application domain. To refine, for example, the generic `logico:isAt` relation to provide more information about our agricultural scenario, we extended AgriCo to provide additional sub-relations for the most important facility types in our model, such as `agrico:onFarm` and `agrico:onField`, which are extracted as explicit semantic facts via an additional set of rules.

Similarily, we can use the same type of reasoning to analyze spatial relations between a pairs of machines. For example, we used SEMAP to detect that a transport vehicle (TV) is correctly positioned for an overloading procedure, due to its directional relations regarding a self-propelled forage harvester (SFH). Fig. 7 exemplifies how to construct this complex domain-specific relation by combining several basic spatial relations with additional domain-dependent knowledge. Fig. 7 (a) depicts the situation of interest in real life, whereas (b) shows visualization of a similar scene represented in SEMAP. To identify that the transport vehicle is properly positioned for overloading, the rule shown in (c) checks the trailer's 2D convex hull for containment in the harvester's `left-of` projection, to verify that the transport vehicle is left-of the harvester. If so, the relation `agrico:positionedForOverloading` is inferred to hold between the transport vehicle and the harvester.

(a) Overloading in reality.



(b) Overloading in RViz.

```
?sfh rdf:type agrico:Harvester
?sfh semap:hasObjectModel ?sfh_obj
?sfh_obj semap:hasLeftOfProjection2D ?sfh_proj_l2D
?tv rdf:type agrico:TransportVehicle
?tv semap:hasObjectModel ?tv_obj
?tv semap:hasConvexHull2D ?tv_abstr_ch2D
?tv_abstr_ch2D semap:isIn2D ?sfh_proj_l2D
==>
?tv agrico:positionedForOverloading ?sfh
```

(c) The rule for grounding the `positionedForOverloading` relation in SEMAP.

Fig. 7: We used telemetry data from an actual overloading procedure (a), to move and articulate the machines in ROS and visualize them in RViz (b). We also synchronized the telemetry with our SEMAP model and used the rule (c) to identify the correct spatial positioning of two machines for overloading harvested goods from a forage harvester onto a transport vehicle.

This kind of reasoning deducts a valuable symbolic representation about the underlying agricultural process, which was previously covert in the telemetry data of both machines. Here, SEMAP's spatio-semantic processing makes this information explicitly available as factual knowledge within SEMAP's KB. Such a representation is useful for further processing, for example, to monitor changes of the spatial relations over time. Especially when looking at logistic problems in harvesting processes, the spatial transitions of resources correspond strongly with the underlying process the machines go through. For example, a transporter arriving at the harvester initiates overloading or being on a silo corresponds to unloading a trailer. To account for such situations, we extended SEMAP's core ontology further to support reasoning about process states in such contexts.

4.4 The AgriServ Ontology

We call this extension the AgriServ ontology, as it allows to describe agricultural work and services in terms of the activities that have to be performed to achieve a certain logistical objective in the agricultural domain. It is again based on work by Daniele et al. [5] and also relies on ideas proposed by Hoxha et al. in [8]. Fig. 8 shows an excerpt of the ontology.

The description of agricultural processes in AgriServ revolves around the concepts of activities and events. The `Activity` concept describes the actionable steps

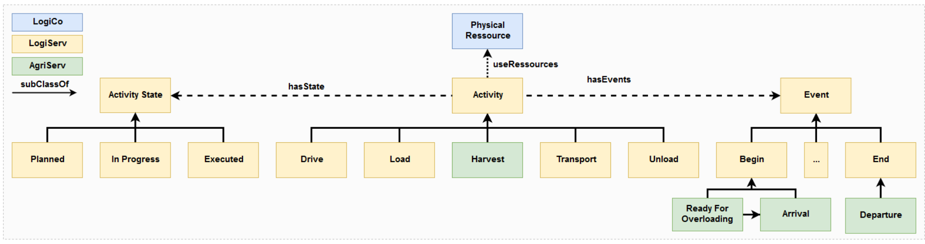


Fig. 8: The AgriServ ontology provides a model of agricultural processes.

of an logistic transport process, i.e., loading goods at a origin location A, transporting them from A to B and unloading them at their destination location B. There are also activities defined that are specific to the agricultural domain, such as harvesting crops. To denote which resources are involved in an activity, the `logiserv:usesResource` relation is used. It maps from the instance of an activity concept to one or many instances of the `PhysicalResource` concept defined in the upper-ontologies LogiCo and AgriCo. This relation can, of course, be further differentiated to specify the requirements towards a certain type of activity. For example, AgriServ defines the relations `hasField`, `hasHarvester` and `hasTransporter` to clarify on the specific roles of the `Overloading` activity. The spatial locations at which the activity begins and ends are denoted through the relations `hasOrigin` and `hasDestination` which point to an instance of `StaticResource`, pointing to one of the agricultural facilities introduced in AgriCo. Likewise, each activity can be annotated with the time frame in which it is valid, using the `hasBegin` and `hasEnd` relation to point to a specific time stamp. The semantics of this time interval may vary due to the status of the given activity. An activity's state is reflected through the `hasState` predicate which points to an element of a fixed set of progress states, namely `Requested`, `Planned`, `In Progress` or `Executed`.

Closely related to the state of an activity are the events associated with it. Each `Event` denotes a significant occurrence during the activity's life cycle and maybe the cause of changing an activity instance's current state. To differentiate between different types of events, AgriServ uses sub-classes. It provides basic event types, such as `Begin`, `End`, `Suspend` and `Resume`, to describe the general progress of an activity. Each factual instance of event identifies a resource as its subject, as well as another resource as its target, if this applicable, like in cooperative activities such as overloading crops from a harvester to a transport vehicle. An event also gives a time stamp and location, denoting when and where it occurs, too.

Activities are described as a sequence of events and hold a list of associated instances via the `hasEvent` relation. This relation is further differentiated by sub-relations, which carry a specific semantic relative to an activity's state. The `hasPlan` relation, for example, maps to all the expected events of a planned activity, whereas the `hasTrigger` relation identifies all events that progress the activity regardless of whether the plan is matched or not. Finally, the `hasActual` relation maps to all events that actually occurred during an activities execution.

This the spatial state transitions of a movable resources within its environment are nothing short of events, it is further useful to provide concepts for spatial events, too. AgriServ provides the events `Arrival`, `Departure`, as spatially

# Time	# Reference	# Spatial Relation	# Event	# Target
13:16:45	tractor1	onFarm	Arrival	farm1
13:16:46	tractor1	onVehicleScale	Arrival	scale
13:16:51	harvester1	onField	Arrival	field2
13:16:53	tractor1	onVehicleScale	Departure	scale
13:16:59	tractor1	onSilo	Arrival	silo_north
13:17:02	tractor2	onField	Arrival	field2
13:17:36	tractor2	inDistance	Arrival	harvester1
13:17:45	tractor2	positionedForOverloading	Arrival	harvester1
13:18:03	tractor1	onSilo	Departure	silo_north
13:18:35	tractor1	onFarm	Departure	farm1
13:20:21	tractor2	positionedForOverloading	Departure	harvester1
13:20:29	tractor2	inDistance	Departure	harvester1
13:21:28	tractor2	onField	Departure	field2

Fig. 9: A continuous trace log of spatial relations between machines and environment created through analyzing telemetry data with SEMAP.

related refinements of the begin and end events, which always need an additional resource assignment to identify the target it is in reference to. Similarly, the `ReadyForOverloading` event is issued based on changes based on the domain-specific spatial relation `positionedForOverloading`.

4.5 Mapping from Spatial Events to Process Events

To inspect the changing relations in our application example, we queried SEMAP for the relevant relations with every incoming telemetry datum. In our experiment, we sampled telemetry data at a rate of 1 hz to generate a continuous trace log of the machines whereabouts and their relations towards each other. This sub sampling was done to reduce the amount of collected data to a reasonable size while keeping enough temporal resolution to trace and detect relevant events.

Fig. 9 gives an example of such a trace. It shows how `tractor1` arrives at the farm, visits the vehicle scale and then continues to drive the silo, as it goes through the process of weighing its load and then unloading it at the silo. The trace shows further, that at the same time `harvester1` is arriving at `field2`, where it is approached by `tractor2` shortly after. This approach can be monitored through different stages, as `tractor1` first comes near the harvester indicated by the `inDistance` relation and then takes the correct position for overloading, as discussed above. In both cases, one the spatial transitions give strong indications about the underlying agricultural process, hence we went on creating spatial events and map them onto the process model.

Since SEMAP's query system is stateless and processes each query on the current world state of the environment model independently, there is no tracking of previous states. Event generation is currently done in an external processing node which accounts for the state history and generates the appropriate events, if a spatial transition occurs. When, for example, the fact `tractor1 isAt farm1` did hold at timestamp t_n, but does not anymore at t_{n+1}, an `Departure` event is created and asserted to the KB, cf., Fig. 9.

In the same way, we approached the detection of process states and events. To trace the harvesting process, an additional processing node was setup to encodes

# Time	# Reference	# Process	# Event	# Target
13:16:45	tractor1	Farmwork	Begin	farm1
13:16:46	tractor1	Weighing	Begin	scale
13:16:51	harvester1	Fieldwork	Begin	field2
13:16:53	tractor1	Weighing	End	scale
13:16:59	tractor1	Unloading	Begin	silo_north
13:17:45	tractor2	Overloading	Begin	harvester1
13:18:03	tractor1	Unloading	End	silo_north
13:18:35	tractor1	Farmwork	End	farm1
13:20:21	tractor2	Overloading	End	harvester1

Fig. 10: A continuous trace log of process events created through analyzing the spatial transitions using a state machine.

a state machine that inspects the spatial events using simple transitioning rules and creates the process events accordingly. Fig. 10 shows the mapping onto the process events for the same dataset, as was used in Fig. 9.

Admittedly, proper integration of such state-aware querying and event handling within the SEMAP framework is not yet realized and subject to future work. However, with this workaround, we were able to track the relevant transitions of the recorded harvesting campaign in terms of our semantic model, while being fully grounded in the spatial relations that where derived through the underlying spatio-semantic knowledge base and querying system.

5 Conclusion and Future Work

In this article, we used the SEMAP framework for combined spatial and semantic reasoning about machine-environment and machine-machine in an agricultural domain. To create a semantic model of agricultural environments and machines, we extended an ontological model from the logistics domain resulting in the agricultural core ontology AgriCo. Based on this semantic model, we instantiated a data set that combined factual knowledge with spatial data in our framework. Using recorded telemetry data, we moved and articulated several agricultural machines to replay a forage maize harvesting campaign. We used SEMAP's spatial operators for quantitative spatial analysis to classify topological relations between fields and machines. We also used an ontological model of logistical and agricultural processes and rule-based reasoning over the changing relations, to detect process states and events relevant to the harvesting process. We exemplified this process by showing how to infer that a transport vehicle is ready for overloading due to its position relative to the harvester.

Our approach demonstrates that the use of semantic mapping technology in agriculture is beneficial, as we were able to extract valuable information about the agricultural process out of the geo-referenced stream of telemetry data. The derived knowledge about machine-machine and machine-environment relations is validated in the geometric state of the environment and also available as machine-readable facts that adhere to a formal ontological model, which opens up possibilities for the further development of decision support systems.

To further improve SEMAP's spatio-semantic querying, temporal information must be included, too. Currently, the data model is updated continuously to represent the environment's current state, but provides neither a history of past states, nor methods to query about temporal change. This denies the possibility to detect events by querying the temporal sequence of certain relations and states directly. For this, we relied on additional processing modules coupled with SEMAP to detect events. Adding a temporal information layer to SEMAP will be a necessary next step to realize proper temporal analysis and event generation. For this, stream reasoning approaches like the Continuous SPARQL framework (CSPARQL) [2] could be used.

We also plan to extend our process-related reasoning to include additional telemetry information besides the machine's geolocation, as this will enable a quantitative assessment of the harvesting process, which would complement our current approach of qualitative evaluation.

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