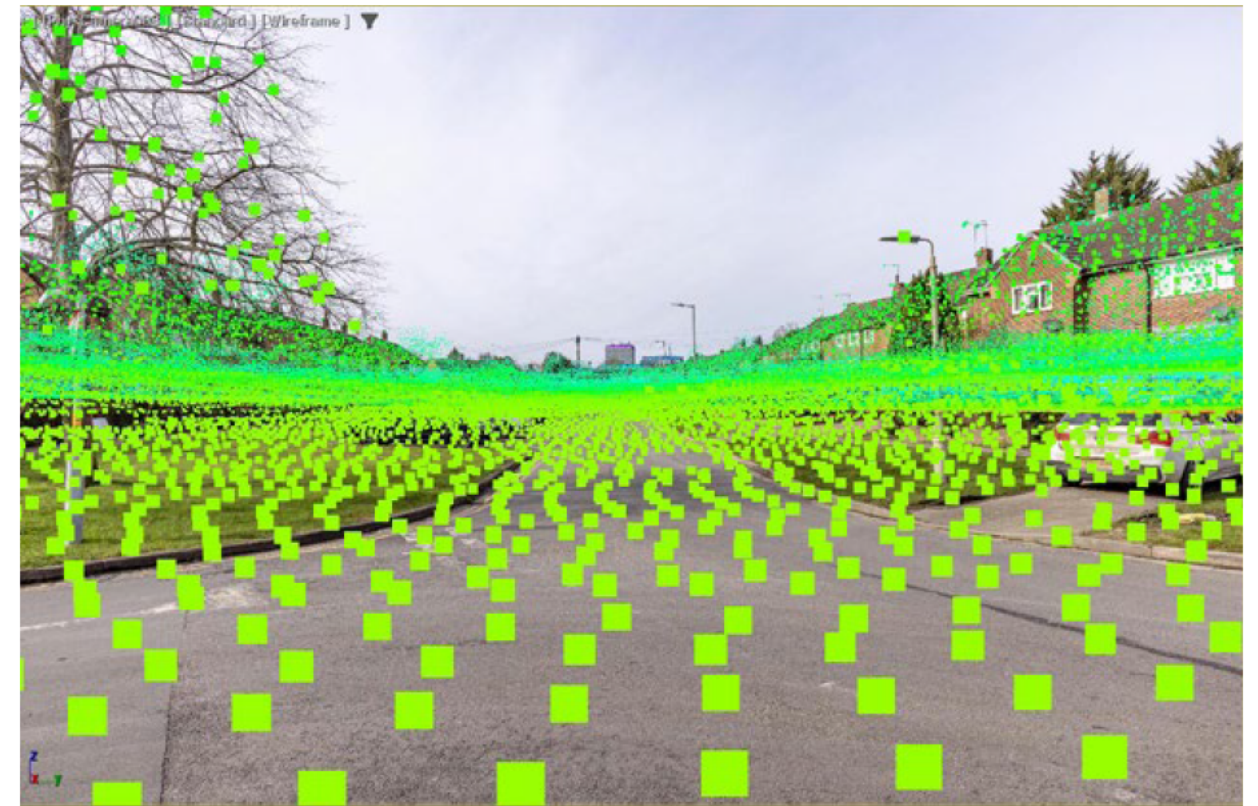




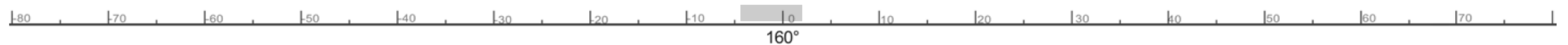
VIEW 6: Carpenter Way



Photo ref: 0717
 Location: 51.692554, -0.167266
 Heading: W / 275°
 AOD Sensor (Ref:OS/Defra): 95.49 m
 ~Distance to site: 760 m
 Time: 11:47:00
 Date: 17/02/2026
 Focal length: 50mm
 AVR Type 4/Level: 1



Point Cloud Overlay



VIEWPOINT PANORAMA





VIEW 7: Southgate Road

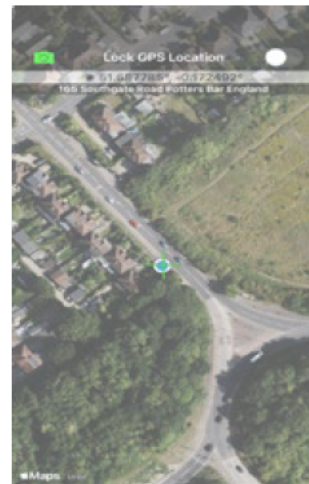
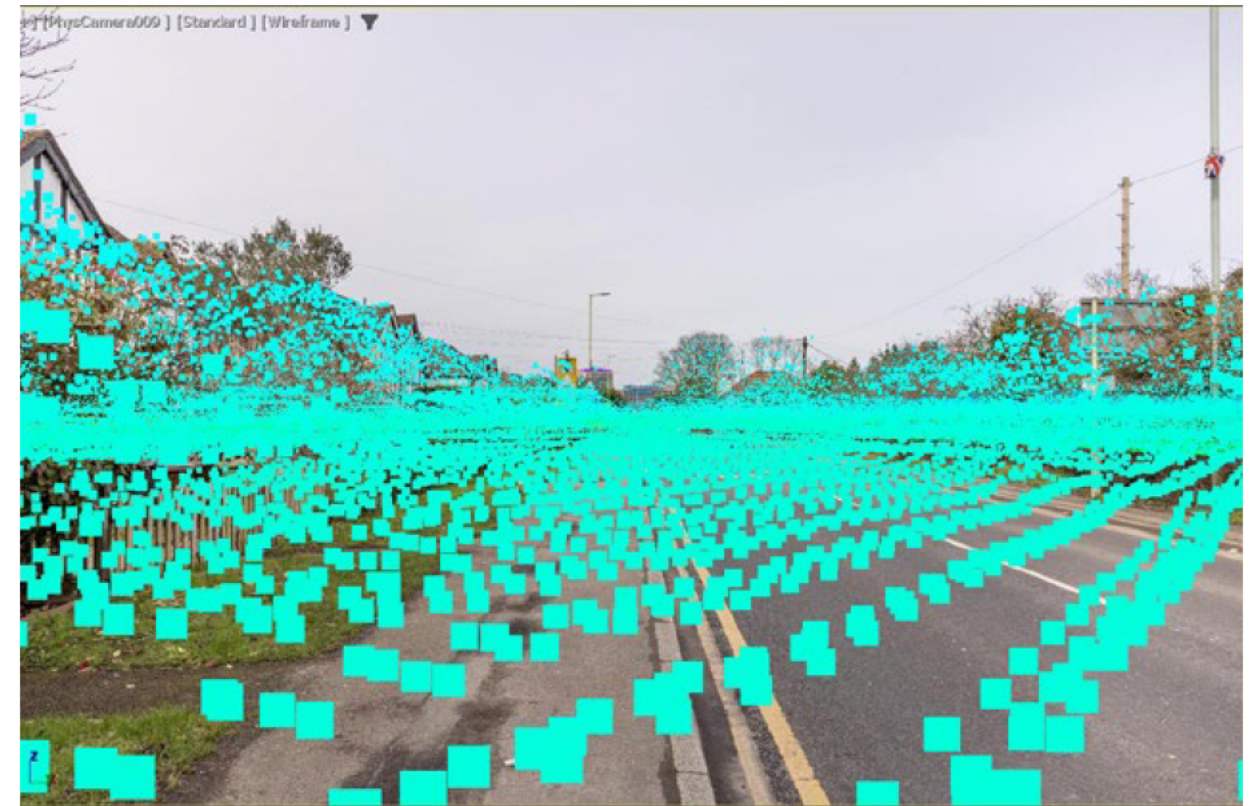
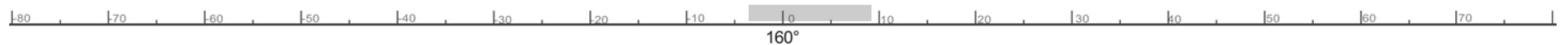


Photo ref: 0737
 Location: 51.687745, -0.172483
 Heading: NW / 320°
 AOD Sensor (Ref:OS/Defra): 124.01 m
 ~Distance to site: 700 m
 Time: 12:06:00
 Date: 17/02/2026
 Focal length: 50mm
 AVR Type 4/Level: 1



Point Cloud Overlay



VIEWPOINT PANORAMA





VIEW 8: Potters Bar Station

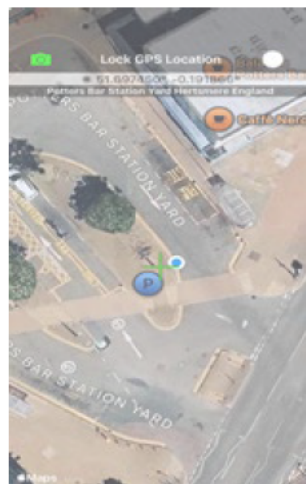
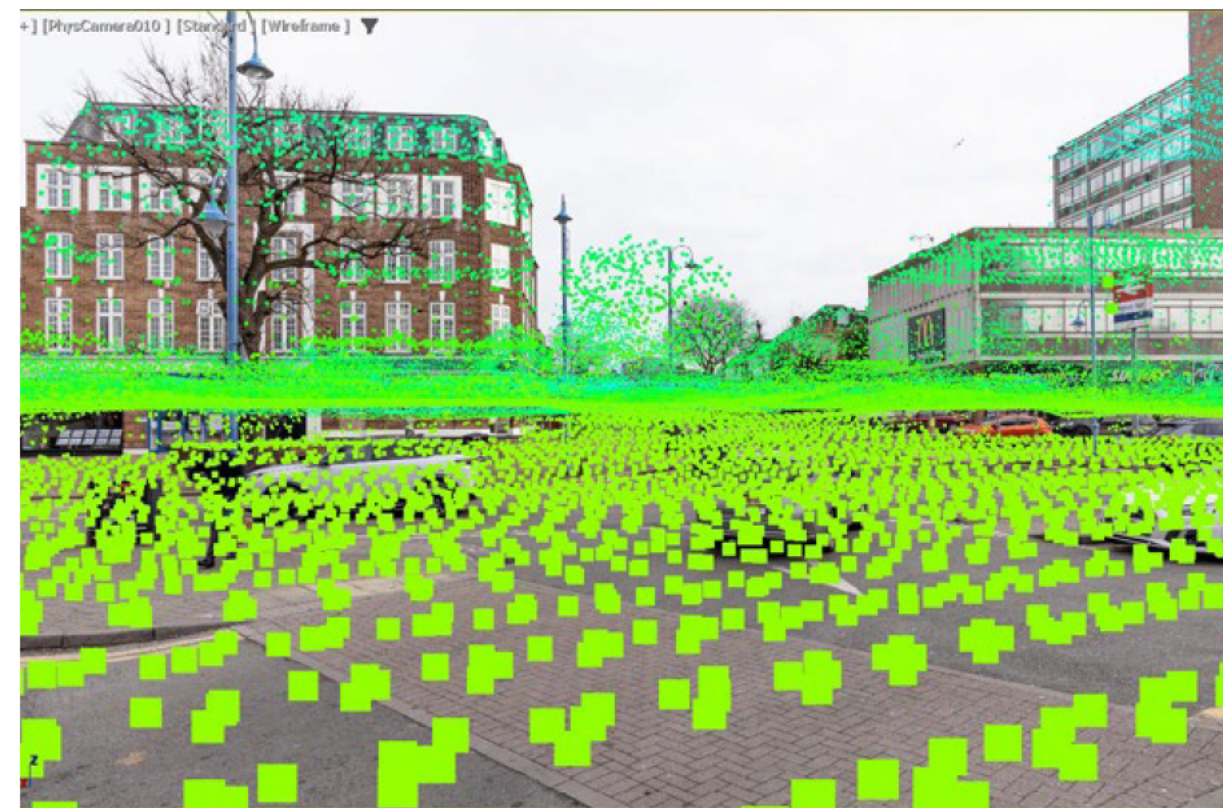
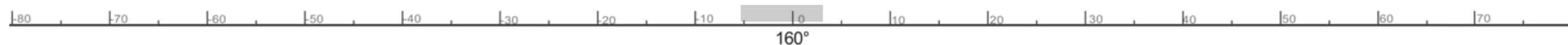


Photo ref: 0897
 Location: 51.697419, -0.191929
 Heading: SE / 126°
 AOD Sensor (Ref:OS/Defra): 96.40 m
 ~Distance to site: 930 m
 Time: 14:51:00
 Date: 17/02/2026
 Focal length: 50mm
 AVR Type 4/Level: 1



Point Cloud Overlay



VIEWPOINT PANORAMA





VIEW 9: Osborne Road

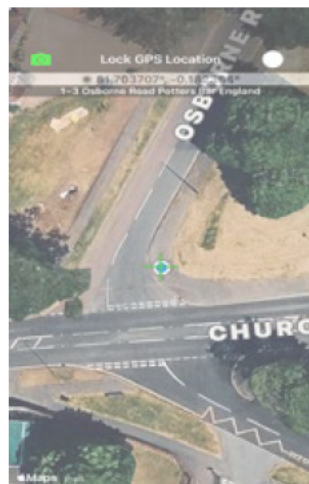
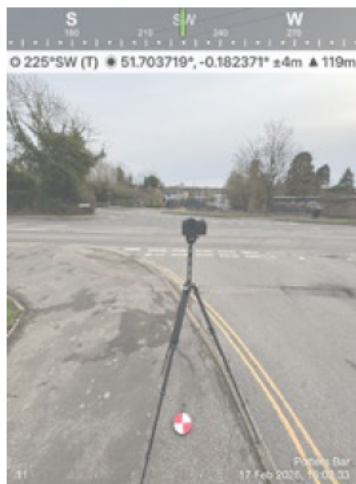
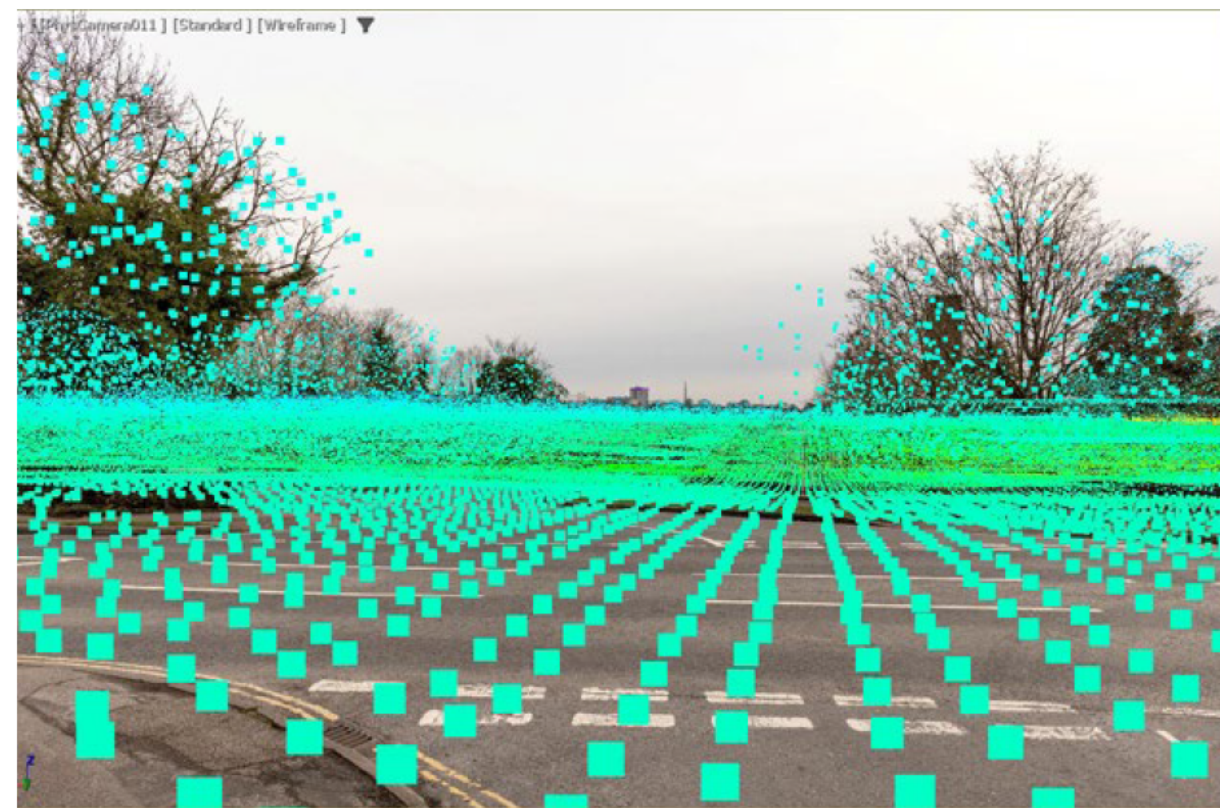
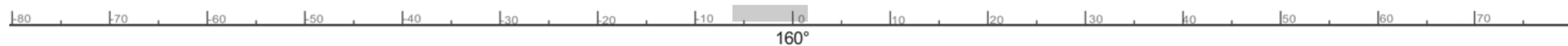


Photo ref: 0937
 Location: 51.703719, -0.182371
 Heading: SW / 225°
 AOD Sensor (Ref:OS/Defra): 120.37 m
 ~Distance to site: 1070 m
 Time: 16:02:00
 Date: 17/02/2026
 Focal length: 50mm
 AVR Type 4/Level: 1



Point Cloud Overlay



VIEWPOINT PANORAMA





VIEW 10: Oakroyde Close

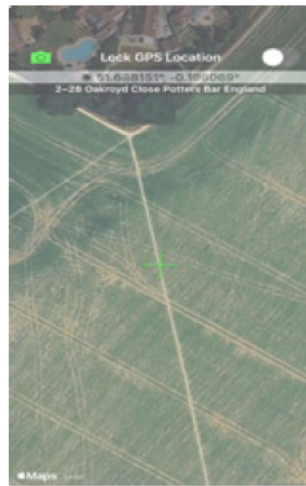
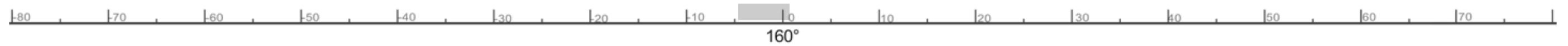


Photo ref: 0877
 Location: 51.688118, -0.196050
 Heading: NE / 54°
 AOD Sensor (Ref:OS/Defra): 108.61 m
 ~Distance to site: 1250 m
 Time: 14:20:00
 Date: 17/02/2026
 Focal length: 50mm
 AVR Type 4/Level: 1



Point Cloud Overlay



VIEWPOINT PANORAMA





VIEW 11: Public footpath from Hawkshead Road

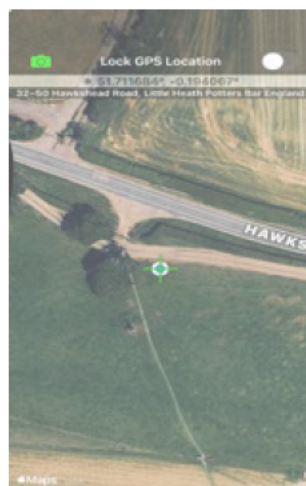
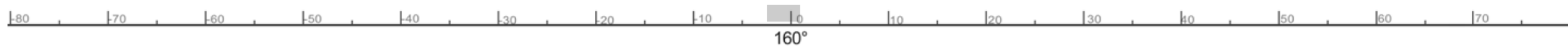


Photo ref: 0917
 Location: 51.711667, -0.194076
 Heading: SE / 152°
 AOD Sensor (Ref:OS/Defra): 113.71 m
 ~Distance to site: 2200 m
 Time: 15:32:00
 Date: 17/02/2026
 Focal length: 50mm
 AVR Type 4/Level: 1



Point Cloud Overlay



VIEWPOINT PANORAMA

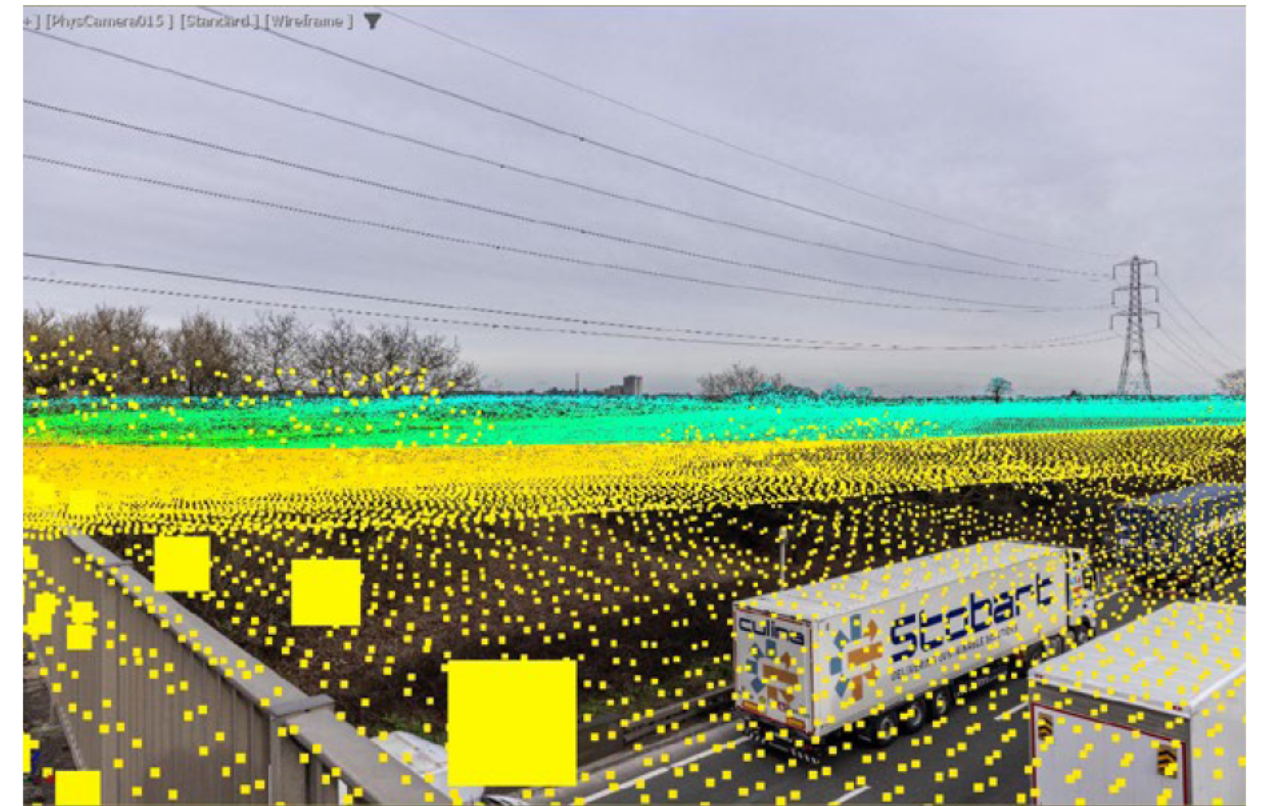




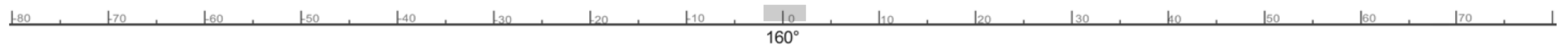
VIEW 12: Footbridge over M25



Photo ref: 0837
 Location: 51.685642, -0.195559
 Heading: E / 70°
 AOD Sensor (Ref:OS/Defra): 124.24 m
 ~Distance to site: 1350 m
 Time: 13:57:00
 Date: 17/02/2026
 Focal length: 50mm
 AVR Type 4/Level: 1



Point Cloud Overlay



VIEWPOINT PANORAMA





Appendix 5: Technical Methodology for Accurate Visual Representations (AVRs) (Ocean AVR)



AVR / Verified Views Methodology

OVERVIEW

OceanAVR uses a methodology that is compliant with relevant sections of: The Landscape Institute Advice Note 06/19 (Visual Representation of Development Proposals).

Digital photographs are taken from the agreed locations.

An adequate number of visible features are subsequently surveyed, in relation to the location of each camera position.

A development 3D computer model is imported to correct geographical co-ordinates.

Virtual cameras are created within the computer model. These are matched to simulate the sensor, exposure settings and lens properties of the real-world camera.

The real-world camera positions are simulated and aligned with the 3D computer model by combining the laser survey with GPS/ GNSS, Lidar & OS data.

The virtual cameras are then used to render views of the model. These rendered views are then blended with the corresponding photography.

PHOTOGRAPHY

For each agreed photoviewpoint location, photographs are taken with a digital SLR camera. The camera is digitally levelled horizontally and laterally. The camera is set on the tripod, fixing the lens at a height of 1.6m above ground.

CAMERA POSITION SURVEY

Exact data corresponding to relative horizontal and vertical distance is recorded for the various reference points visible within the photograph and GPS/GNSS location data is gathered. Reference photographs of the camera in-situ are taken at each camera location. A handheld 3D Lidar scan is also created at each viewpoint location to capture the camera within its immediate surrounding context.

Equipment Used for Photography

- Canon EOS-5D Mark III DSLR full-frame camera
- Canon EF 50mm 1:1.2 L USM fixed lens
- Canon EF 24mm f/1.4L II USM fixed lens
- Manfrotto 190 Go carbon Tripod/Manfrotto MHXPRO-3WG Head

Survey Equipment

- Global Positioning System (GPS) Canon GP-E2 camera-mounted
- Leica Disto D810 / Leica Zeno 20 / Leica Disto s910

THE PROPOSED DEVELOPMENT

A development 3D computer model is produced by OceanAVR using CAD information provided by the project architect. Alternatively the 3D model is supplied to OceanAVR by the project architect.

A 3D computer model of the wider area including existing levels and built features is created using digital OS resources combined with the on-site laser survey. Alternatively this can be supplied by 3rd party, (eg; City Vision Networks, ZMapping) created using stereo satellite photography.

ALIGNING THE MODEL AND THE PHOTOGRAPH

The collected survey reference point and camera location data is imported into the 3D software.

Using the EXIF data recorded with each photograph, the virtual camera and lens settings are matched with the physical camera and lens.

Two images for each camera location are then rendered; one showing the proposal in isolation, the other showing the reference point information which is then checked against the photograph to check accuracy.

Using a photo editing package, namely Adobe Photoshop CSS, the photography, rendered survey reference points and proposed development are aligned.

OCCCLUSION AND PERCEPTION OF THE PROPOSED VIEW

Level 0 - Shows mass and position within the context of the photograph

Level 1 - Shows mass, position and visibility

Level 2 - Shows mass, position, visibility and architectural detail

Level 3 - Shows mass, position, visibility, architectural form, photo-realistic materials and daylight

Applicable to Level 2 and Level 3 images

With the rendered proposals aligned to the photography, a mask is applied to hide aspects of the proposed development that would be occluded by existing features.

Applicable to Level 3 images

Within the limits of current technology and available data, techniques and experienced judgement are employed by the visualiser to manipulate the rendered image so that it appears as photorealistic as possible.

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