3D Modeling

COS 426

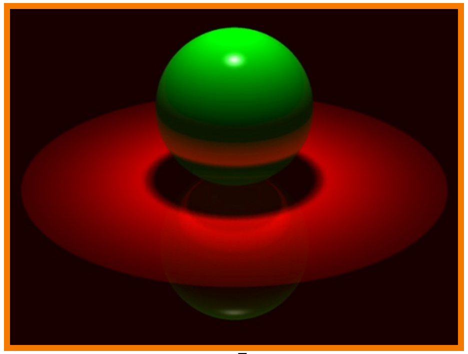
Syllabus

I. Image processing

II. Modeling

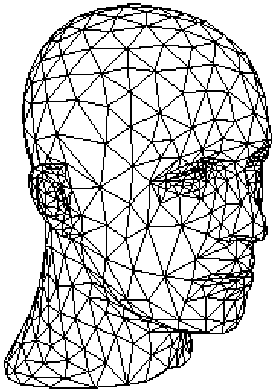
III. Rendering

IV. Animation

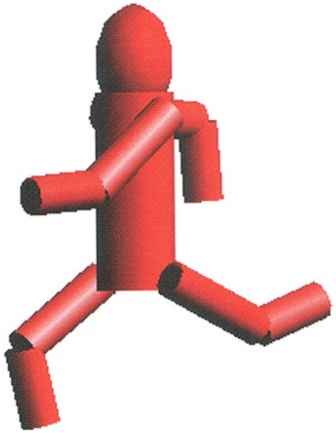


Rendering
(Michael Bostock, CS426, Fall99)

Image Processing
(Rusty Coleman, CS426, Fall99)



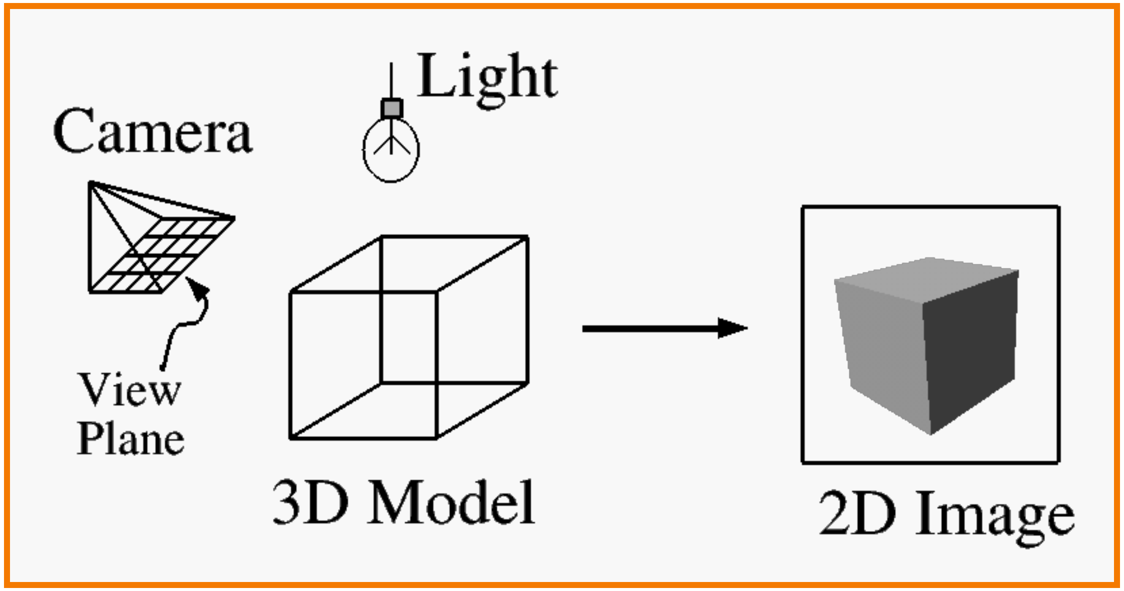
Modeling
(Dennis Zorin, CalTech)



Animation
(Angel, Plate 1)

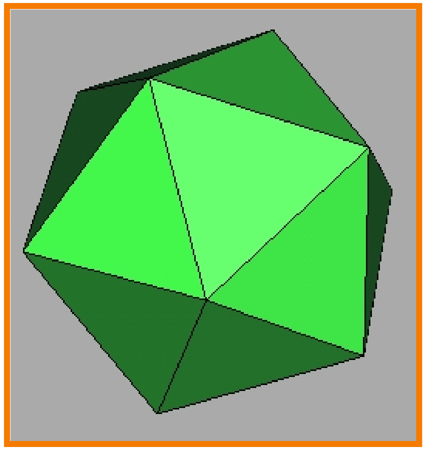
What is 3D Modeling?

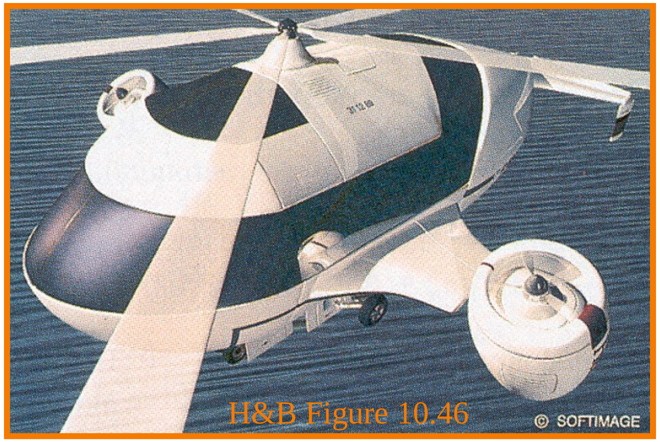
- Topics in computer graphics
  - Imaging = *representing 2D images*
  - Rendering = *constructing 2D images from 3D models*
  - Modeling = *representing 3D objects*
  - Animation = *simulating changes over time*



Modeling

- How do we ...
  - Represent 3D objects in a computer?
  - Acquire computer representations of 3D objects?
  - Manipulate computer representations of 3D objects?





H&B Figure 10.46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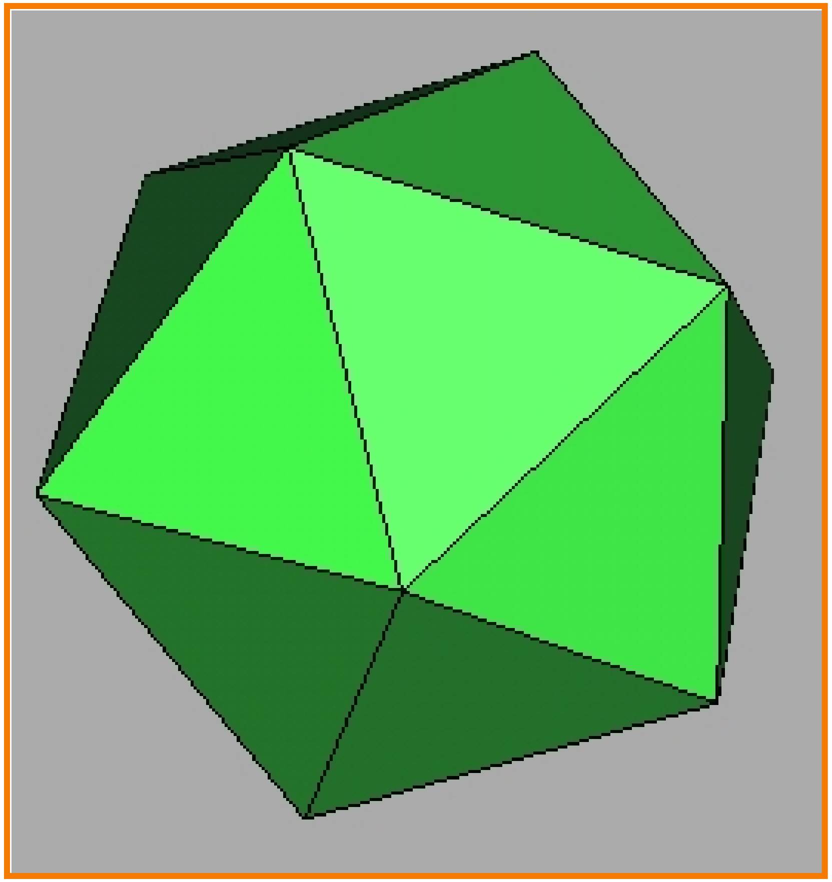
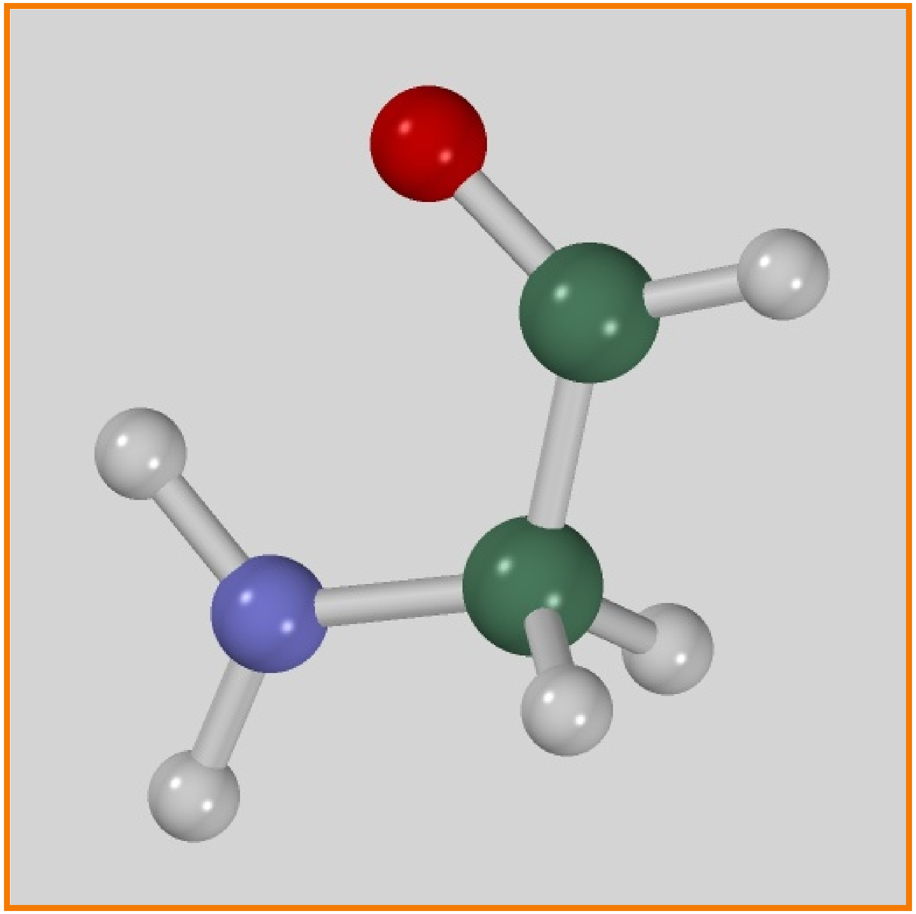
3D Object Representations



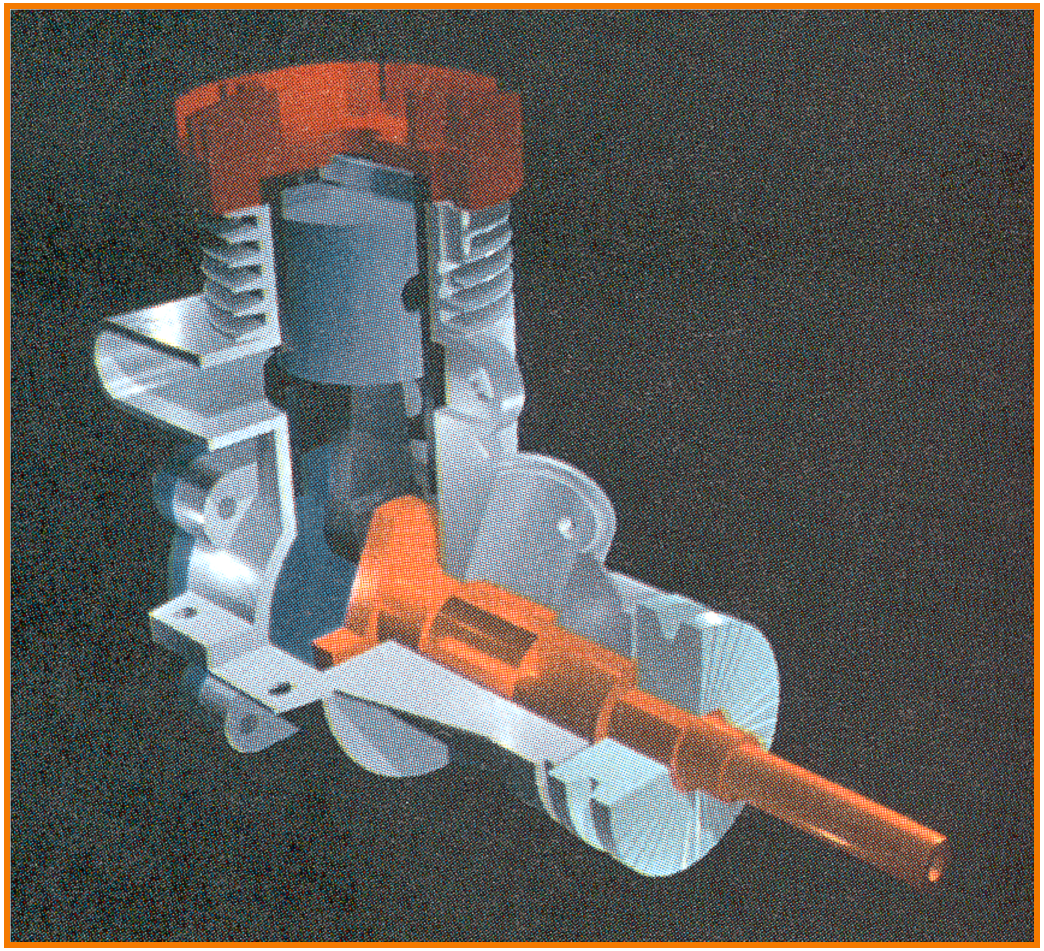
How can this object be represented in a computer?

3D Object Representations



How about this one?

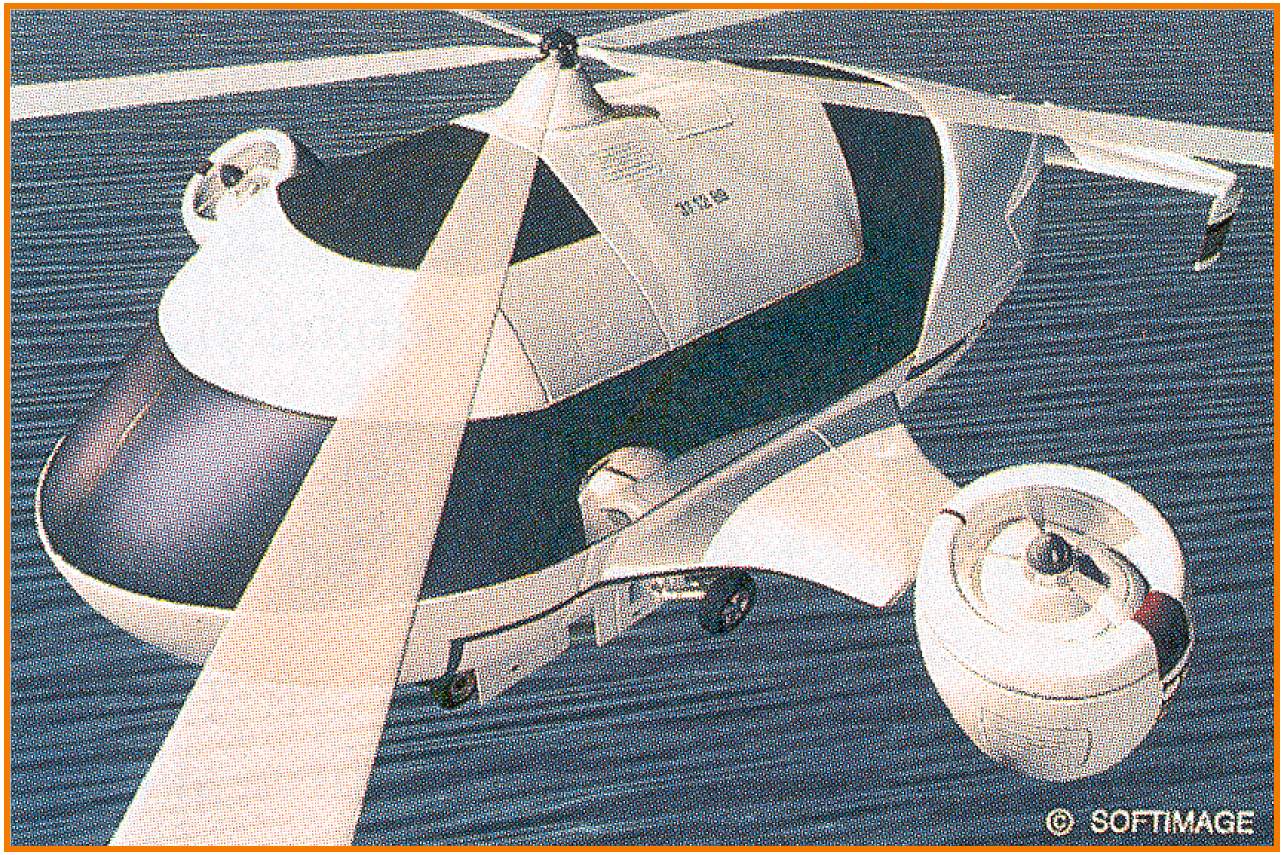
3D Object Representations



H&B Figure 9.9

This one?

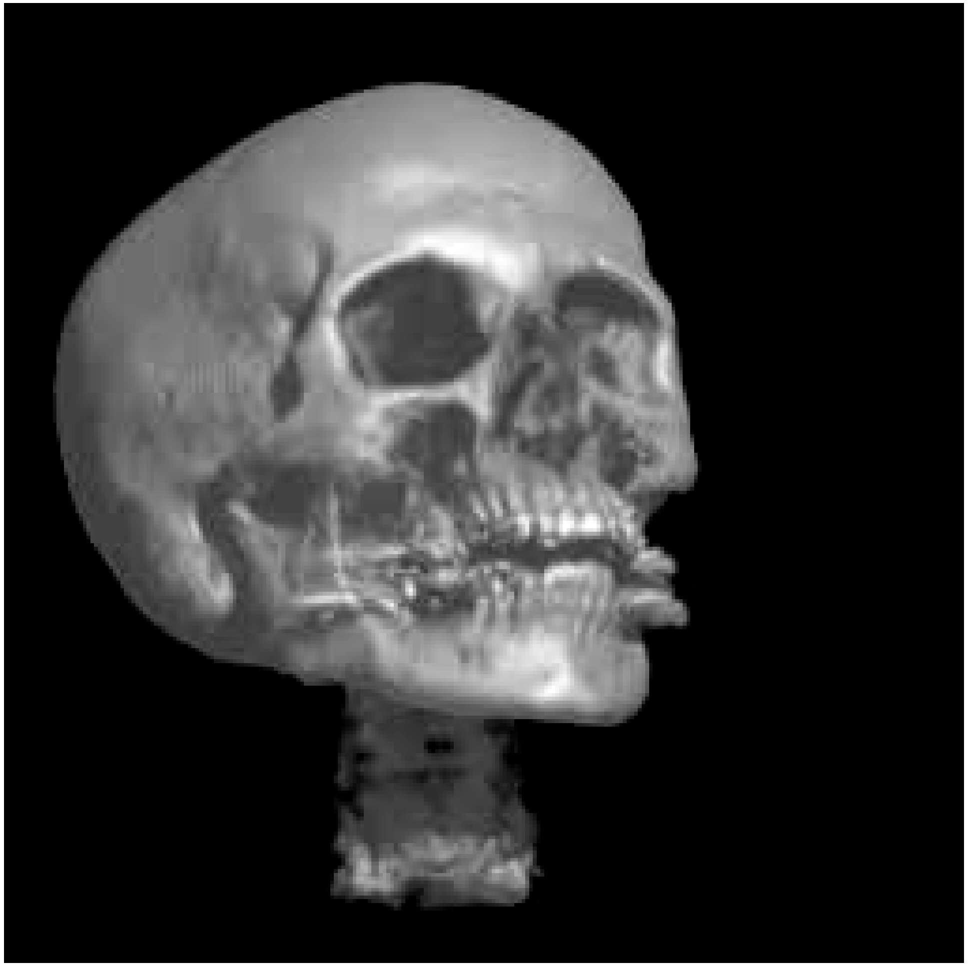
3D Object Representations



H&B Figure 10.46

This one?

3D Object Representations



This one?

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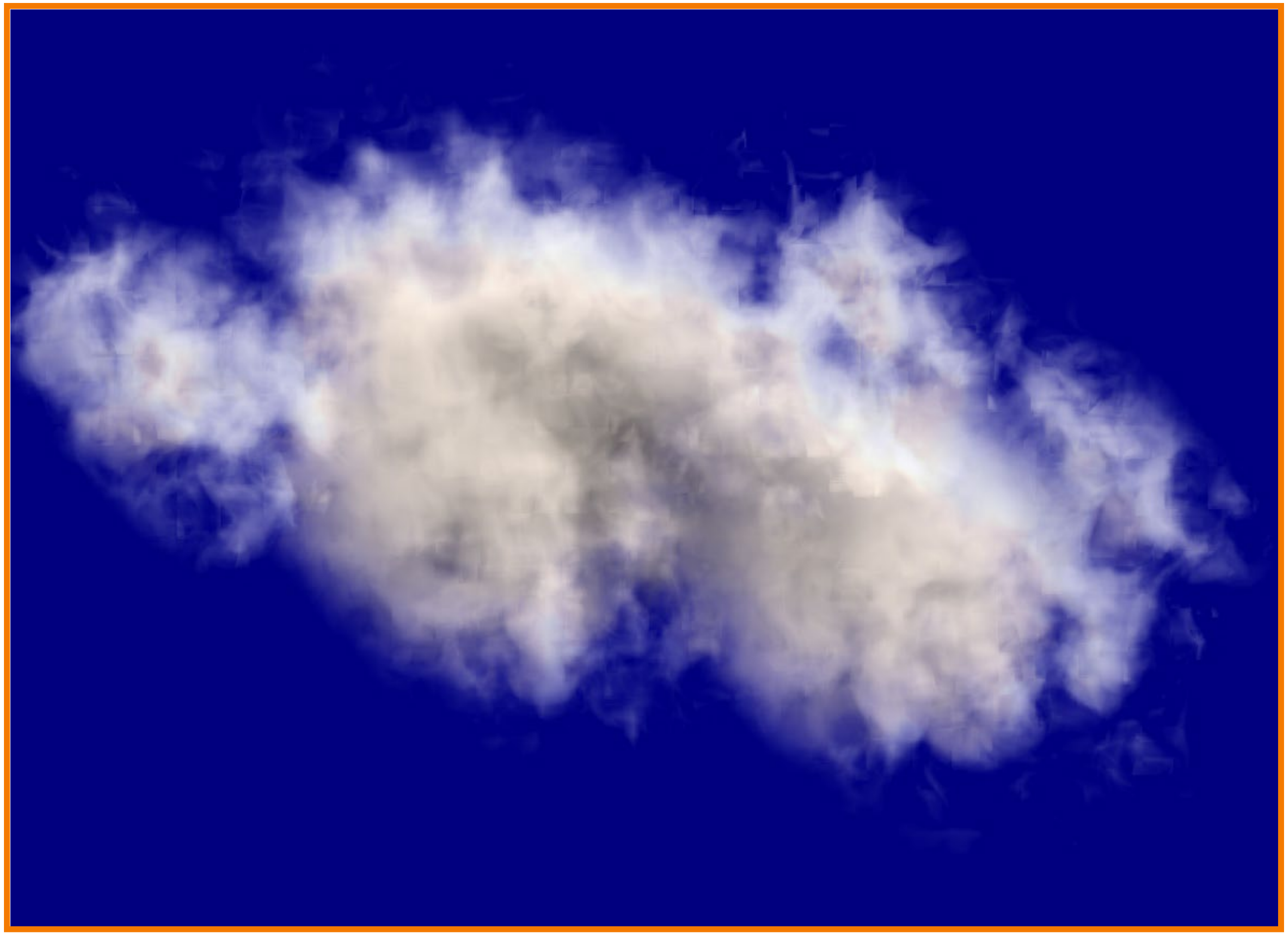
3D Object Representations



This one?

3D Object Representations

- Points
  - Range image
  - Point cloud
- Surfaces
  - Polygonal mesh
  - Subdivision
  - Parametric
  - Implicit
- Solids
  - Voxels
  - BSP tree
  - CSG
  - Sweep
- High-level structures
  - Scene graph
  - Application specific

Equivalence of Representations

- Thesis:
  - Each representation has enough expressive power to model the shape of any geometric object
  - It is possible to perform all geometric operations with any fundamental representation
- Analogous to Turing-equivalence
  - Computers and programming languages are Turing-equivalent, but each has its benefits…

Why Different Representations?

Efficiency for different tasks

- Acquisition
- Rendering
- Manipulation
- Animation
- Analysis

Data structures determine algorithms

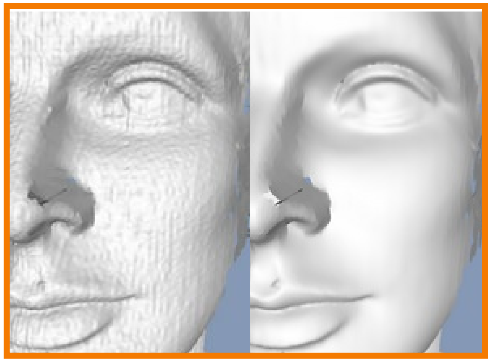
Modeling Operations

What can we do with a 3D object representation?

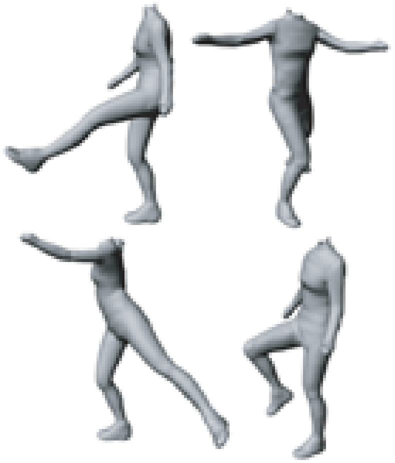
- Edit
- Transform
- Smooth
- Render
- Animate
- Morph
- Compress
- Transmit
- Analyze
- etc.

Digital Michelangelo

Pirates of the Caribbean



Thouis “Ray” Jones

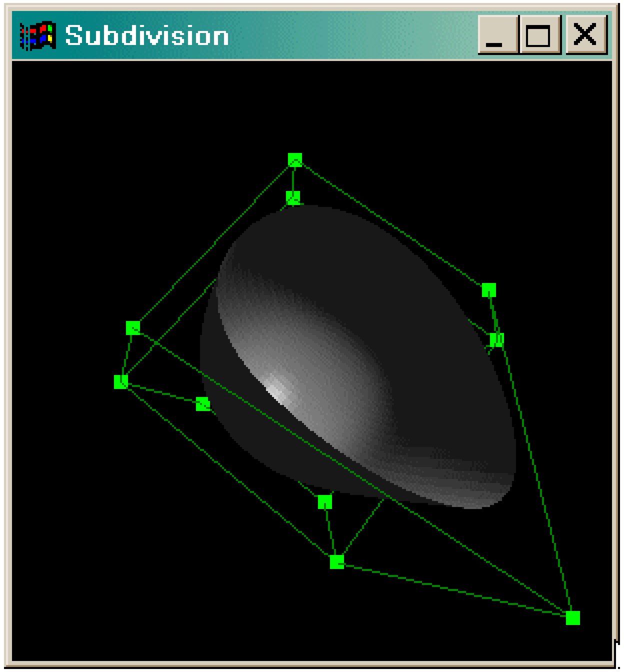


Sand et al.

3D Object Representations

Desirable properties depend on intended use

- Easy to acquire
- Accurate
- Concise
- Intuitive editing
- Efficient editing
- Efficient display
- Efficient intersections
- Guaranteed validity
- Guaranteed smoothness
- etc.



Outline

- Points
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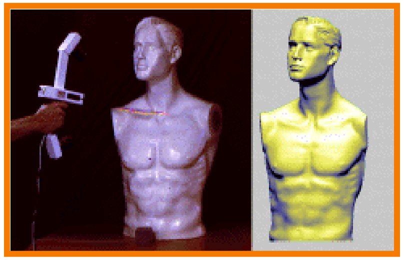
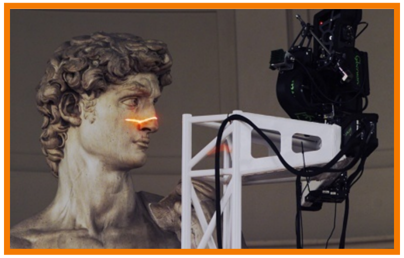
Range Image

Set of 3D points mapping to pixels of depth image

- Can be acquired from range scanner



Cyberware



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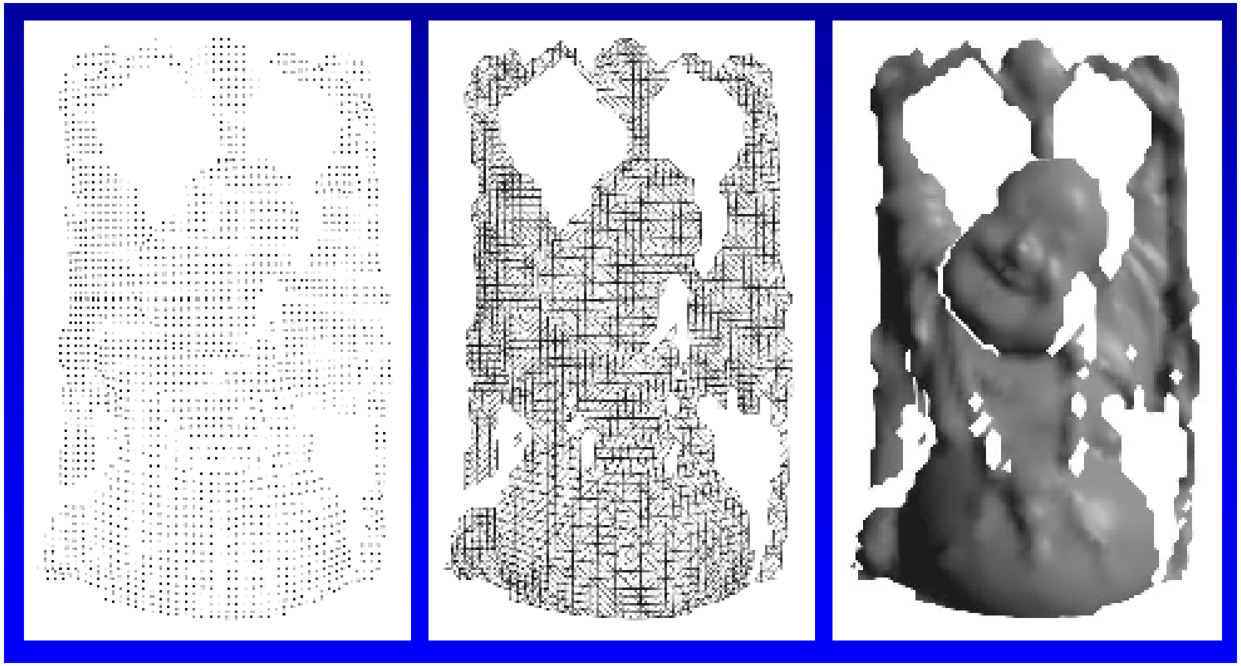


Range Image Tesselation Range Surface

Brian Curless
SIGGRAPH 99
Course #4 Notes

Range Image

- Image: stores an intensity / color along each of a set of regularly-spaced rays in space
- Range image: stores a depth along each of a set of regularly-spaced rays in space

- Not a complete 3D description: does not store objects occluded (from some viewpoint)
- *View-dependent* scene description

Terminology

- Range images
- Range surfaces
- Depth images
- Depth maps
- Height fields
- 2½-D images
- Surface profiles
- xyz maps
- …

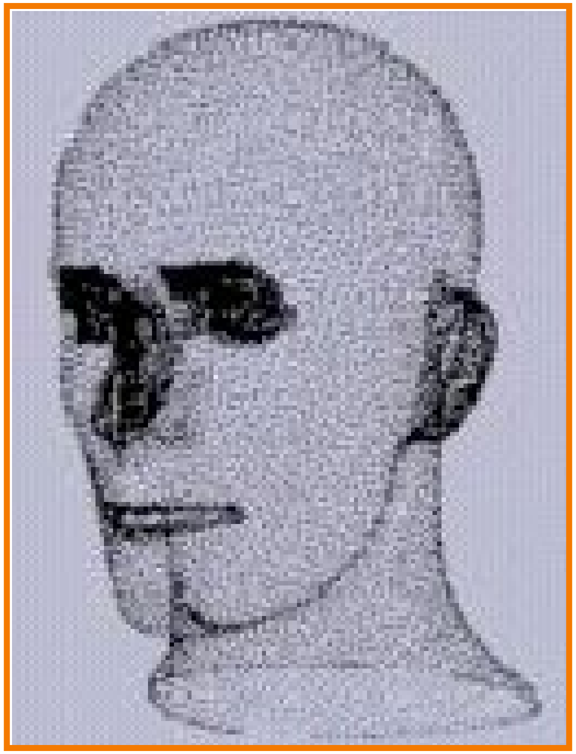
Point Cloud

Unstructured set of 3D point samples

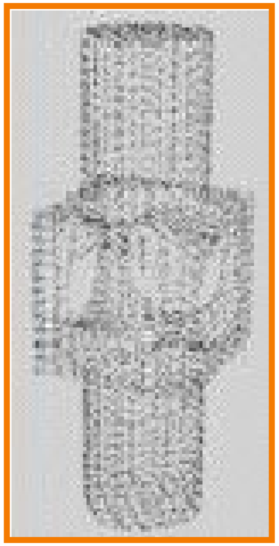
- Acquired from range finder, computer vision, etc

Polhemus

Microscribe-3D



Hoppe



Hoppe

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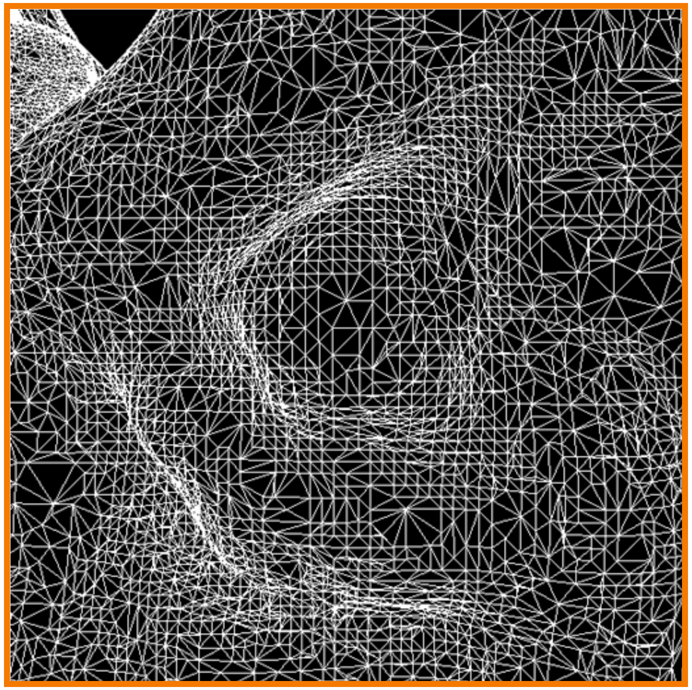
Polygonal Mesh

Connected set of polygons (usually triangles)



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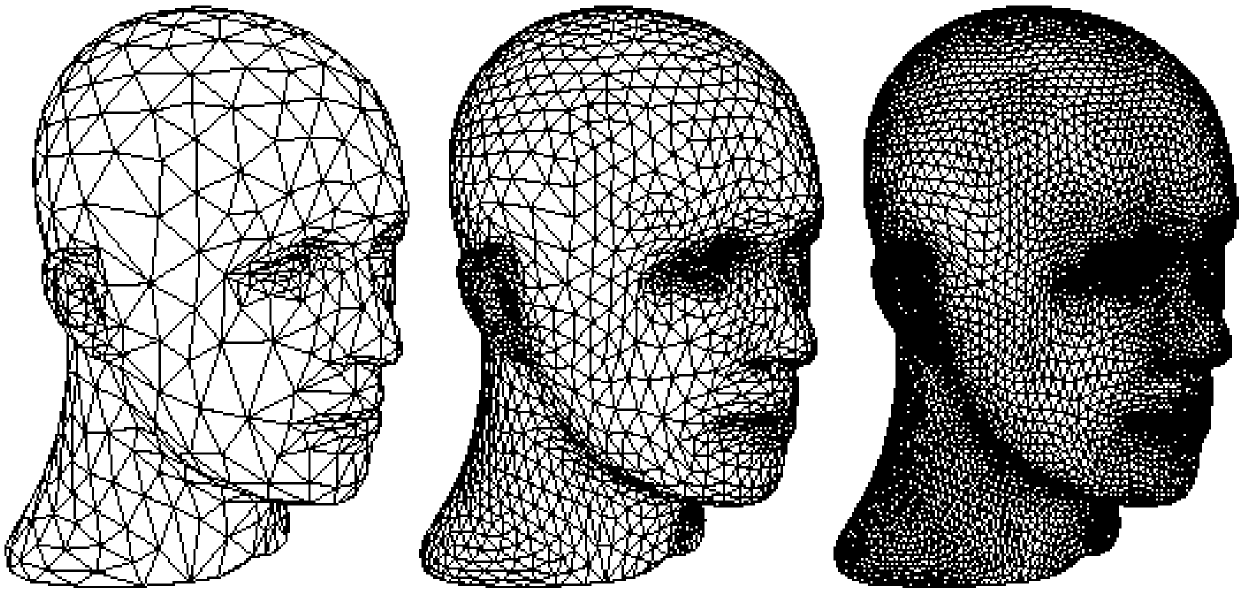
Subdivision Surface

Coarse mesh & subdivision rule

- Smooth surface is limit of sequence of refinements

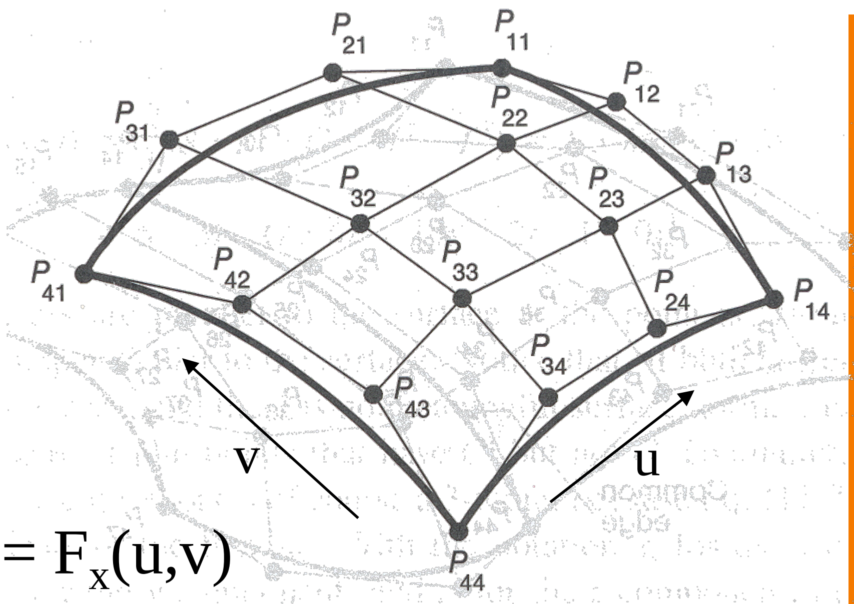


Zorin & Schroeder
SIGGRAPH 99
Course Notes

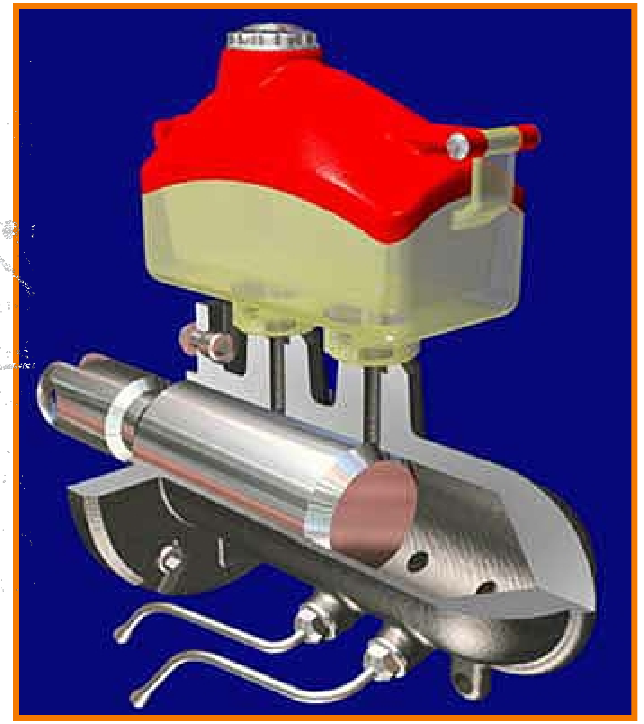
Parametric Surface

Tensor-product spline patches

- Each patch is parametric function
- Careful constraints to maintain continuity



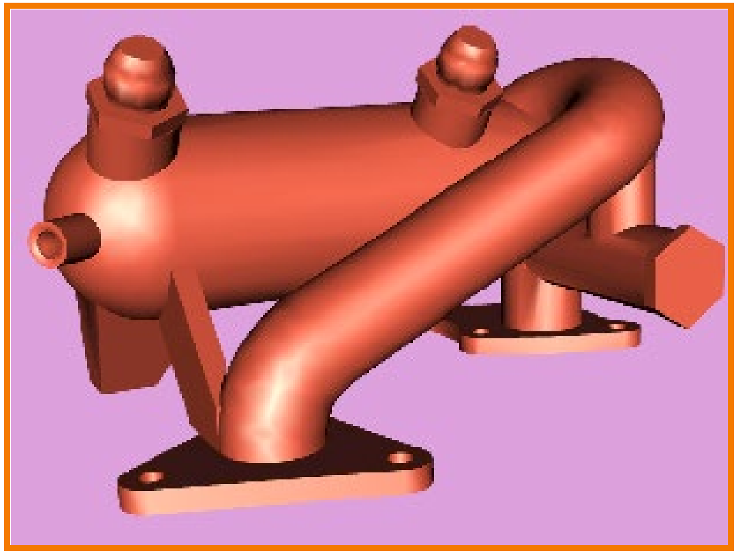
$$x = F_x(u,v)$$
$$y = F_y(u,v)$$
$$z = F_z(u,v)$$



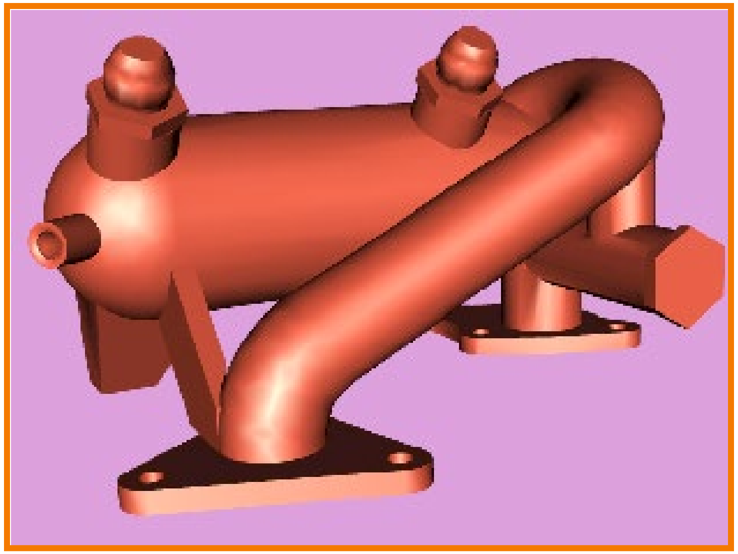
FvDFH Figure 11.44

Implicit Surface

Set of all points satisfying: F(x,y,z) = 0



Polygonal Model



Implicit Model

Bill Lorensen
SIGGRAPH 99
Course #4 Notes

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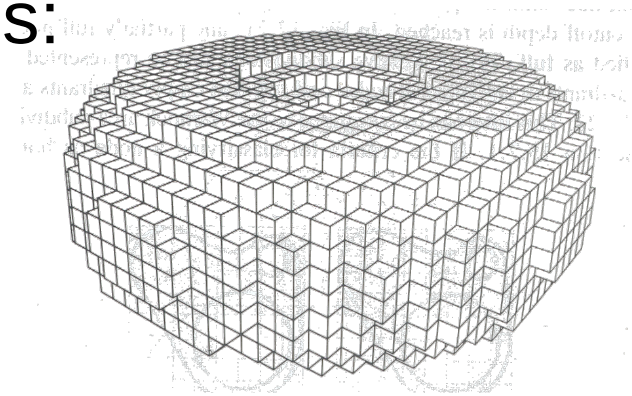
Voxel grid

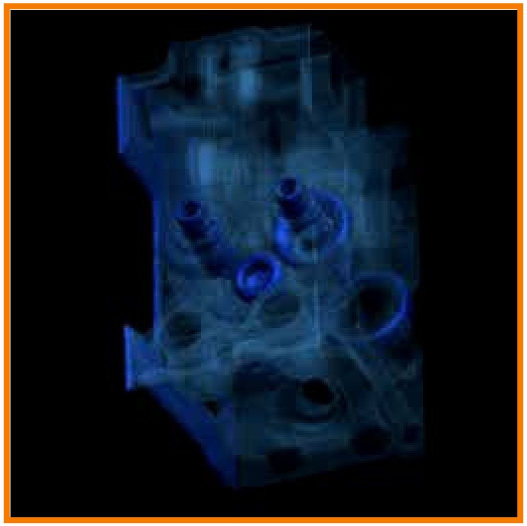
Uniform volumetric grid of samples:

- Occupancy
  (object vs. empty space)
- Density
- Color
- Other function
  (speed, temperature, etc.)

- Often acquired via simulation or from CAT, MRI, etc.



FvDFH Figure 12.20



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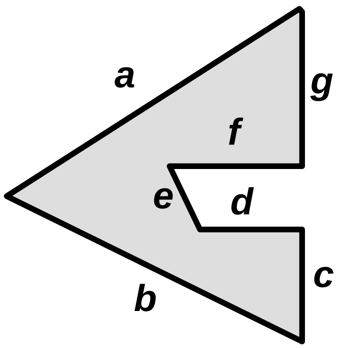
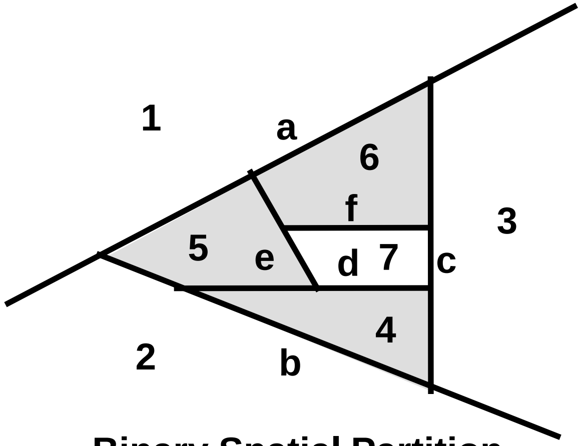
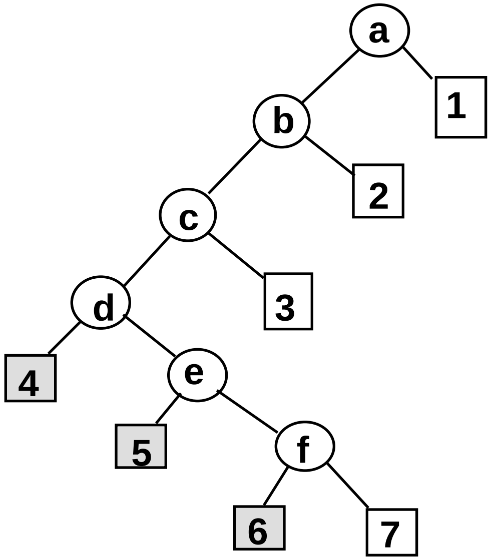
BSP Tree

Hierarchical **B**inary **S**pace **P**artition with solid/empty cells labeled

- Constructed from polygonal representations



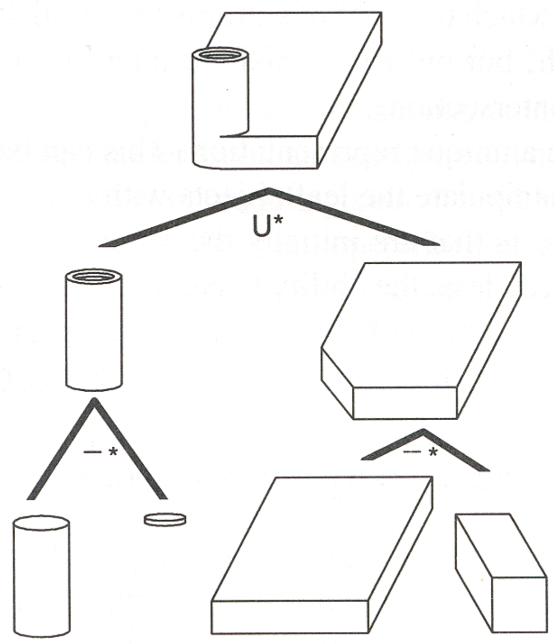




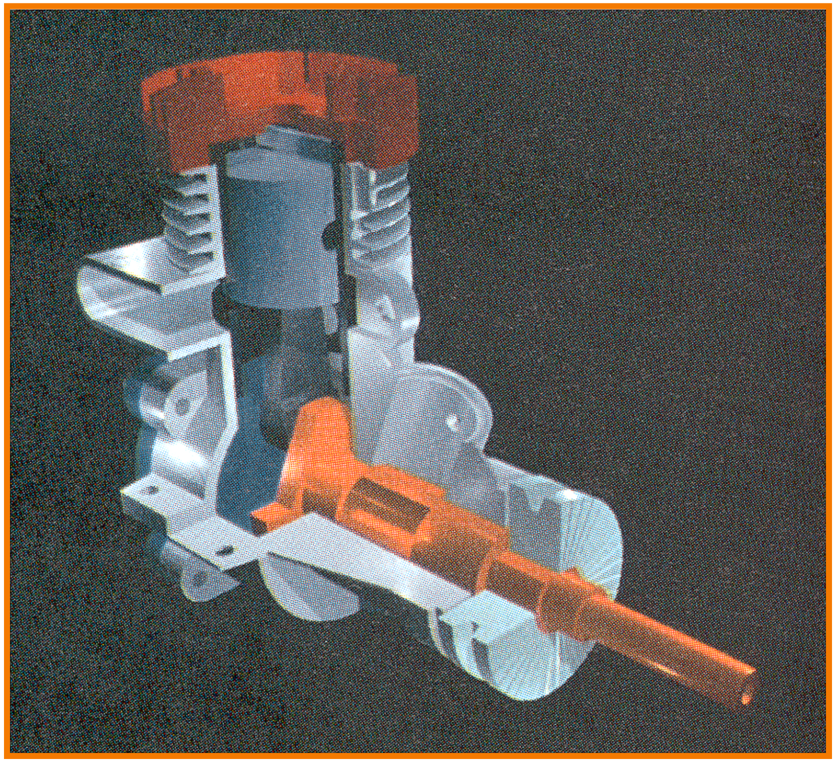
Naylor

CSG

Constructive **S**olid **G**eometry: set operations (union, difference, intersection applied to simple shapes



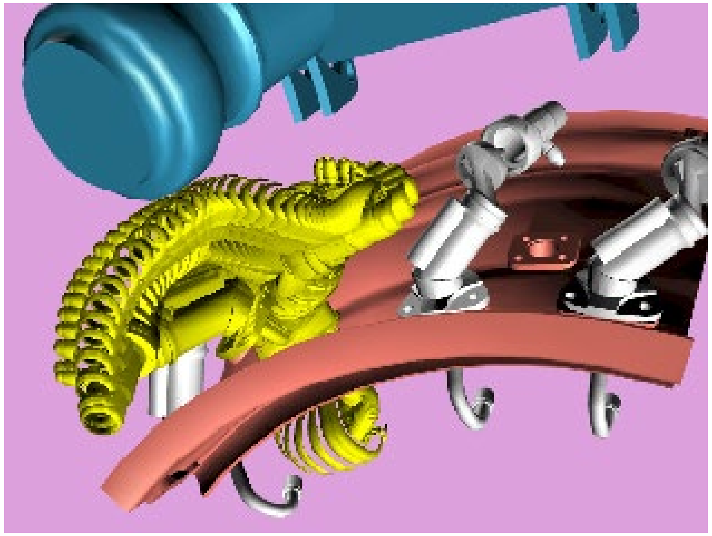
FvDFH Figure 12.27



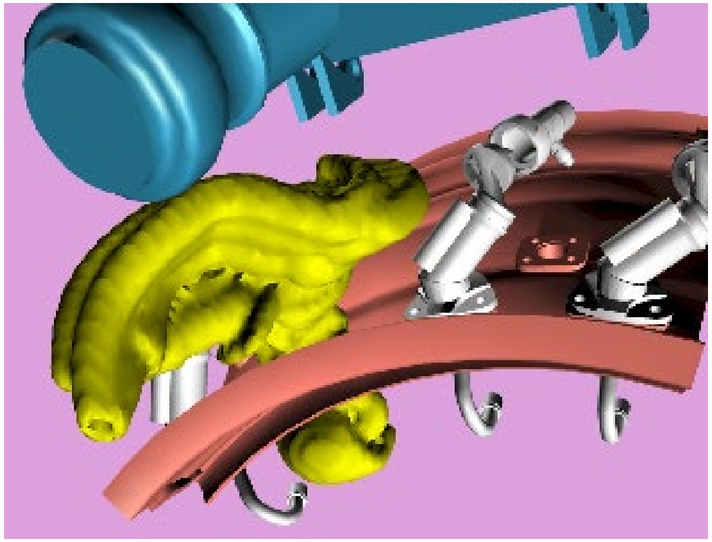
H&B Figure 9.9

Sweep

Solid swept by curve along trajectory



Removal Path



Sweep Model

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Scene Graph

Union of objects at leaf nodes

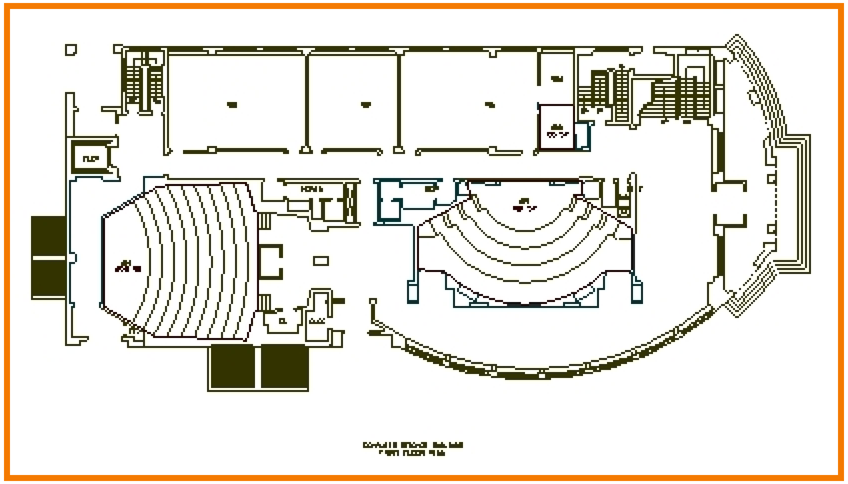
Bell Laboratories

avalon.viewpoint.com

Application Specific

Apo A-1

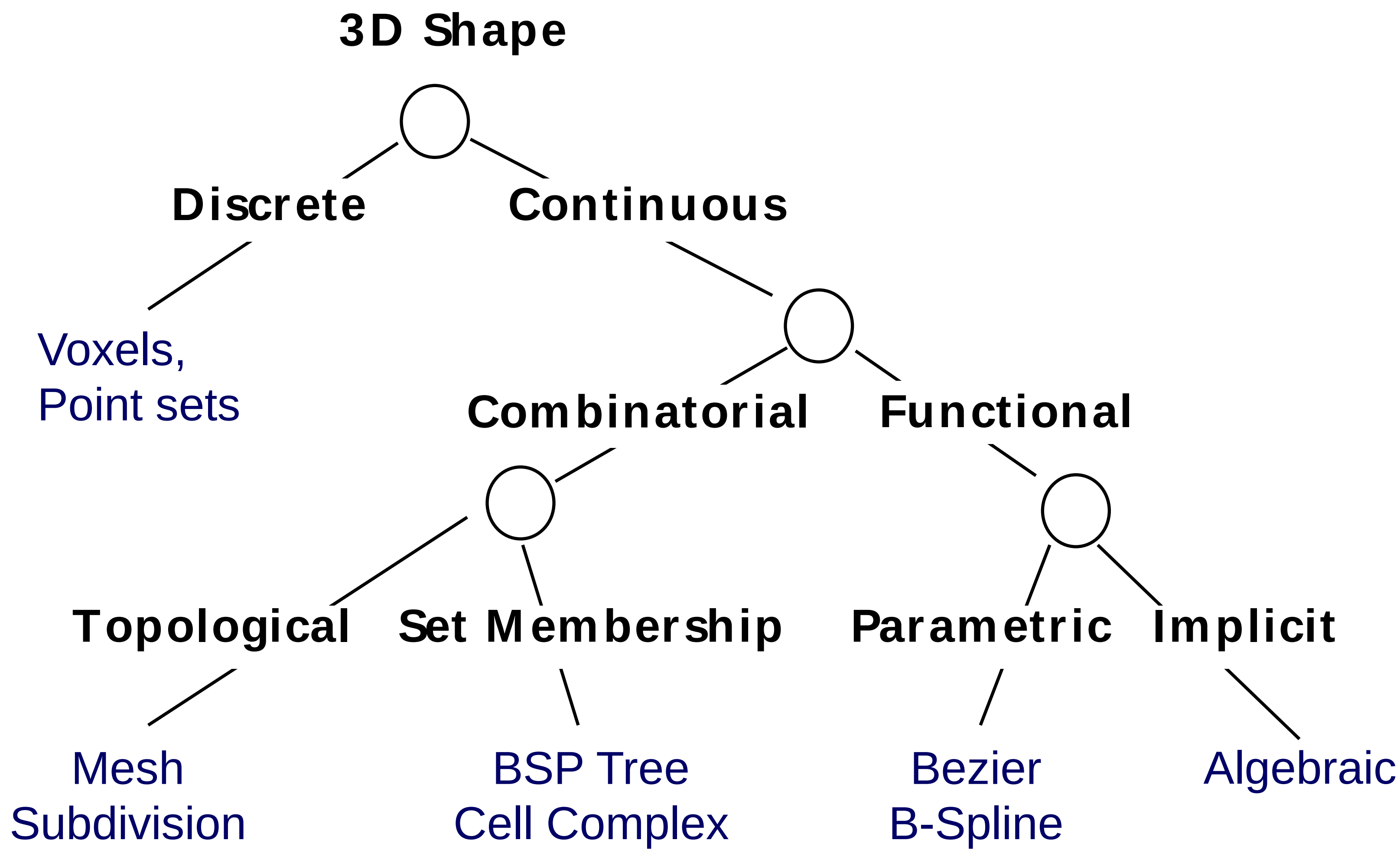
(Theoretical Biophysics Group, University of Illinois at Urbana-Champaign)



Architectural Floorplan

(CS Building, Princeton University)

Taxonomy of 3D Representations



Naylor

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Computational Differences

- Efficiency
  - Representational complexity (e.g. volume vs. surface)
  - Computational complexity (e.g. $O(n^2)$ vs $O(n^3)$)
  - Space/time trade-offs (e.g. z-buffer)
  - Numerical accuracy/stability (e.g. degree of polynomial)
- Simplicity
  - Ease of acquisition
  - Hardware acceleration
  - Software creation and maintenance
- Usability
  - Designer interface vs. computational engine

Upcoming Lectures

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