Ray Casting

COS 426, Spring 2016
Princeton University
Ray Casting

- The color of each pixel on the view plane depends on the radiance emanating along rays from visible surfaces in scene.
Scene

- Scene has:
  - Scene graph with surface primitives
  - Set of lights
  - Camera

```c
struct R3Scene {
    R3Node *root;
    vector<R3Light *> lights;
    R3Camera camera;
    R3Box bbox;
    R3Rgb background;
    R3Rgb ambient;
};
```
Scene Graph

- Scene graph is hierarchy of nodes, each with:
  - Bounding box (in node’s coordinate system)
  - Transformation (4x4 matrix)
  - Shape (mesh, sphere, … or null)
  - Material (more on this later)
Scene Graph

• Simple scene graph implementation:

```c
struct R3Node {
    struct R3Node *parent;
    vector<struct R3Node *> children;
    R3Shape *shape;
    R3Matrix transformation;
    R3Material *material;
    R3Box bbox;
};
```

```c
struct R3Shape {
    R3ShapeType type;
    R3Box *box;
    R3Sphere *sphere;
    R3Cylinder *cylinder;
    R3Cone *cone;
    R3Mesh *mesh;
};
```
Ray Casting

- For each sample (pixel) ...
  - Construct ray from eye position through view plane
  - Compute radiance leaving first point of intersection between ray and scene
Ray Casting

• Simple implementation:

```cpp
R2Image *RayCast(R3Scene *scene, int width, int height) {
    R2Image *image = new R2Image(width, height);
    for (int i = 0; i < width; i++) {
        for (int j = 0; j < height; j++) {
            R3Ray ray = ConstructRayThroughPixel(scene->camera, i, j);
            R3Rgb radiance = ComputeRadiance(scene, &ray);
            image->SetPixel(i, j, radiance);
        }
    }
    return image;
}
```
Ray Casting

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            R3Rgb radiance = ComputeRadiance(scene, &ray);
            image->SetPixel(i, j, radiance);
        }
    }
    return image;
}
```
Constructing Ray Through a Pixel

Ray: $P = P_0 + tV$
Constructing Ray Through a Pixel

• 2D Example

\[ \Theta = \text{frustum half-angle} \]
\[ d = \text{distance to view plane} \]
\[ \text{right} = \text{towards} \times \text{up} \]

\[ P_1 = P_0 + d \times \text{towards} - d \times \tan(\Theta) \times \text{right} \]
\[ P_2 = P_0 + d \times \text{towards} + d \times \tan(\Theta) \times \text{right} \]

\[ P = P_1 + ((i + 0.5) / \text{width}) \times (P_2 - P_1) \]
\[ V = (P - P_0) / \|P - P_0\| \]
(d cancels out…)

Ray: \[ P = P_0 + tV \]
Ray Casting

• Simple implementation:

```cpp
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            R3Ray ray = ConstructRayThroughPixel(scene->camera, i, j);
            R3Rgb radiance = ComputeRadiance(scene, &ray);
            image->SetPixel(i, j, radiance);
        }
    }
    return image;
}
```
Ray Casting

- Simple implementation:

```c
R3Rgb ComputeRadiance(R3Scene *scene, R3Ray *ray)
{
    R3Intersection intersection = ComputeIntersection(scene, ray);
    return ComputeRadiance(scene, ray, intersection);
}

struct R3Intersection {
    bool hit;
    R3Node *node;
    R3Point position;
    R3Vector normal;
    double t;
};
```

Camera  Light  Surfaces
Ray Casting

- Simple implementation:

```c
R3Rgb ComputeRadiance(R3Scene *scene, R3Ray *ray)
{
    R3Intersection intersection = ComputeIntersection(scene, ray);
    return ComputeRadiance(scene, ray, intersection);
}
```

```c
struct R3Intersection {
    bool hit;
    R3Node *node;
    R3Point position;
    R3Vector normal;
    double t;
};
```
Ray Intersection

• Ray Intersection
  ◦ Sphere
  ◦ Triangle
  ◦ Box
  ◦ Scene

• Ray Intersection Acceleration
  ◦ Bounding volumes
  ◦ Uniform grids
  ◦ Octrees
  ◦ BSP trees
Ray Intersection

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  ➢ Sphere
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Ray-Sphere Intersection

\[ P_0 \quad \mathbf{v} \quad P \quad P' \quad O \quad r \]
Ray-Sphere Intersection

Ray: \( P = P_0 + tV \)
Sphere: \( |P - O|^2 - r^2 = 0 \)
Ray-Sphere Intersection I

Ray: $P = P_0 + tV$
Sphere: $|P - O|^2 - r^2 = 0$

Substituting for $P$, we get:

$$|P_0 + tV - O|^2 - r^2 = 0$$

Solve quadratic equation:

$$at^2 + bt + c = 0$$

where:

$$a = V^2$$
$$b = 2 \, V \cdot (P_0 - O)$$
$$c = |P_0 - C|^2 - r^2 = 0$$

$$P = P_0 + tV$$
Ray: \( P = P_0 + tV \)
Sphere: \(|P - O|^2 - r^2 = 0\)

\[ L = O - P_0 \]

\[ t_{ca} = L \cdot V \]
if \( t_{ca} < 0 \) return 0

\[ d^2 = L \cdot L - t_{ca}^2 \]
if \( d^2 > r^2 \) return 0

\[ t_{hc} = \sqrt{r^2 - d^2} \]

\[ t = t_{ca} - t_{hc} \text{ and } t_{ca} + t_{hc} \]

\( P = P_0 + tV \)
Ray-Sphere Intersection

- Need normal vector at intersection for lighting calculations

\[ N = \frac{(P - O)}{\|P - O\|} \]
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Ray-Triangle Intersection
Ray-Triangle Intersection

• First, intersect ray with plane
• Then, check if intersection point is inside triangle
Ray-Plane Intersection

Ray: \( \mathbf{P} = \mathbf{P}_0 + t\mathbf{V} \)
Plane: \( \mathbf{P} \cdot \mathbf{N} + d = 0 \)

Substituting for \( \mathbf{P} \), we get:
\[
(\mathbf{P}_0 + t\mathbf{V}) \cdot \mathbf{N} + d = 0
\]

Solution:
\[
t = -\frac{(\mathbf{P}_0 \cdot \mathbf{N} + d)}{(\mathbf{V} \cdot \mathbf{N})}
\]
\[
\mathbf{P} = \mathbf{P}_0 + t\mathbf{V}
\]
Ray-Triangle Intersection I

- Check if point is inside triangle algebraically

For each side of triangle

\[ V_1 = T_1 - P_0 \]
\[ V_2 = T_2 - P_0 \]
\[ N_1 = V_2 \times V_1 \]

Normalize \( N_1 \)

Plane \( p(P_0, N_1) \)

if \((\text{SignedDistance}(p, P) < 0))\)
    return FALSE
end

return TRUE
Ray-Triangle Intersection II

- Check if point is inside triangle algebraically

For each side of triangle:

\[ V_1 = T_1 - P \]
\[ V_2 = T_2 - P \]
\[ N_1 = V_2 \times V_1 \]

if \((V \cdot N_1 < 0)\)
  return FALSE

end
return TRUE
Ray-Triangle Intersection II

- Check if point is inside triangle algebraically

For each side of triangle

\[ V_1 = T_1 - P \]
\[ V_2 = T_2 - P \]
\[ N_1 = V_2 \times V_1 \]

if \((V \cdot N_1 < 0)\)

return FALSE

end

return TRUE

\[ P \]
\[ T_1 \]
\[ T_2 \]
\[ T_3 \]
\[ V \]
\[ V_1 \]
\[ V_2 \]
\[ N_1 \]
\[ P_0 \]
Ray-Triangle Intersection III

• Check if point is inside triangle parametrically

“Barycentric coordinates” $\alpha$, $\beta$, $\gamma$:

$P = \alpha T_3 + \beta T_2 + \gamma T_1$

where $\alpha + \beta + \gamma = 1$

$\alpha = \frac{\text{Area}(T_1 T_2 P)}{\text{Area}(T_1 T_2 T_3)}$

$\beta = \frac{\text{Area}(T_1 PT_3)}{\text{Area}(T_1 T_2 T_3)}$

$\gamma = \frac{\text{Area}(PT_2 T_3)}{\text{Area}(T_1 T_2 T_3)}$

$= 1 - \alpha - \beta$
Ray-Triangle Intersection III

- Check if point is inside triangle parametrically

Compute “barycentric coordinates” $\alpha$, $\beta$:

$\alpha = \frac{\text{Area}(T_1T_2P)}{\text{Area}(T_1T_2T_3)}$
$\beta = \frac{\text{Area}(T_1PT_3)}{\text{Area}(T_1T_2T_3)}$

$\text{Area}(T_1T_2T_3) = \frac{1}{2} \| (T_2-T_1) \times (T_3-T_1) \|$

check if backfacing:

$((T_2-T_1) \times (T_3-T_1)) \cdot N < 0$

Check if point inside triangle.

$0 \leq \alpha \leq 1$ and $0 \leq \beta \leq 1$

and $\alpha + \beta \leq 1$
Ray Intersection

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  ✅ Box
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Ray-Box Intersection

• Check front-facing sides for intersection with ray and return closest intersection (least $t$)
Ray-Box Intersection

- Check front-facing sides for intersection with ray and return closest intersection (least t)
  - Find intersection with plane
  - Check if point is inside rectangle
Ray-Box Intersection

- **Check** front-facing sides for intersection with ray and return closest intersection (least t)
  - Find intersection with plane
  - Check if point is inside rectangle
Other Ray-Primitive Intersections

- Cone, cylinder:
  - Similar to sphere
  - Must also check end caps

- Convex polygon
  - Same as triangle (check point-in-polygon algebraically)
  - Or, decompose into triangles, and check all of them

- Mesh
  - Compute intersection for all polygons
  - Return closest intersection (least $t$)
Ray Intersection

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  ○ Box
  ➢ Scene

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Ray-Scene Intersection

- Intuitive method
  - Compute intersection for all nodes of scene graph
  - Return closest intersection (least t)
Ray-Scene Intersection

- Scene graph is a DAG
  - Traverse with recursion
R3Intersection ComputeIntersection(R3Scene *scene, R3Node *node, R3Ray *ray)
{
    // Check for intersection with shape
    shape_intersection = Intersect node’s shape with ray
    if (shape_intersection is a hit) closest_intersection = shape_intersection
    else closest_intersection = infinitely far miss

    // Check for intersection with children nodes
    for each child node
        // Check for intersection with child contents
        child_intersection = ComputeIntersection(scene, child, ray);
        if (child_intersection is a hit and is closer than closest_intersection)
            closest_intersection = child_intersection;

    // Return closest intersection in tree rooted at this node
    return closest_intersection
}
Ray-Scene Intersection

- Scene graph can have transformations
Ray-Scene Intersection

- Scene graph node can have transformations
  - Transform ray (not primitives) by inverse of M
  - Intersect in coordinate system of node
  - Transform intersection by M
R3Intersection ComputeIntersection(R3Scene *scene, R3Node *node, R3Ray *ray)
{
    // Transform ray by inverse of node’s transformation

    // Check for intersection with shape

    // Check for intersection with children nodes

    // Transform intersection by node’s transformation

    // Return closest intersection in tree rooted at this node
}
R3Intersection ComputeIntersection(R3Scene *scene, R3Node *node, R3Ray *ray) {
    // Transform ray by inverse of node’s transformation
    // Check for intersection with shape
    // Check for intersection with children nodes
    // Transform intersection by node’s transformation
    // Return closest intersection in tree rooted at this node
}

Note: directions (including ray direction and surface normal $N$) must be transformed by inverse transpose of $M$
Ray Intersection

- Ray Intersection
  - Sphere
  - Triangle
  - Box
  - Scene

- Ray Intersection Acceleration
  - Bounding volumes
  - Uniform grids
  - Octrees
  - BSP trees
Ray Intersection Acceleration

• What if there are a lot of nodes?

http://www.3dm3.com
Bounding Volumes

- Check for intersection with simple bounding volume first
Bounding Volumes

- Check for intersection with bounding volume first
Bounding Volumes

- Check for intersection with bounding volume first
  - If ray doesn’t intersect bounding volume, then it can’t intersect its contents
Bounding Volumes

- Check for intersection with bounding volume first
  - If already found a primitive intersection closer than intersection with bounding box, then skip checking contents of bounding box
Bounding Volume Hierarchies

• Scene graph has hierarchy of bounding volumes
  - Bounding volume of interior node contains all children
Bounding Volume Hierarchies

• Checking bounding volumes hierarchically (within each node) can greatly accelerate ray intersection
R3Intersection ComputeIntersection(R3Scene *scene, R3Node *node, R3Ray *ray)
{
    // Transform ray by inverse of node’s transformation
    // Check for intersection with shape

    // Check for intersection with children nodes
    for each child node
        // Check for intersection with child bounding box first
        bbox_intersection = Intersect child’s bounding box with ray
        if (bbox_intersection is a miss or further than closest_intersection) continue

        // Check for intersection with child contents
        child_intersection = ComputeIntersection(scene, child, ray);
        if (child_intersection is a hit and is closer than closest_intersection)
            closest_intersection = child_intersection;

    // Transform intersection by node’s transformation
    // Return closest intersection in tree rooted at this node
}
Sort Bounding Volume Intersections

- Sort child bounding volume intersections and then visit child nodes in front-to-back order
- Why?
Cache Node Intersections

- For each node, store closest child intersection from previous ray and check that node first.
Bounding Volumes

• Common primitives are:
  ◦ Axis-aligned bounding box
  ◦ Sphere

• What are the tradeoffs?
  ◦ Sphere has simple/efficient intersection code
  ◦ Bounding box is generally “tighter”
Ray Intersection

• Ray Intersection
  ◦ Sphere
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  ◦ Box
  ◦ Scene

• Ray Intersection Acceleration
  ◦ Bounding volumes
  ➢ Uniform grids
  ◦ Octrees
  ◦ BSP trees
Uniform Grid

• Construct uniform grid over scene
  ◦ Index primitives according to overlaps with grid cells
Uniform Grid

- Trace rays through grid cells
  - Fast
  - Incremental

Only check primitives in intersected grid cells
Uniform Grid

• Potential problem:
  ◦ How choose suitable grid resolution?

Too little benefit if grid is too coarse

Too much cost if grid is too fine
Ray Intersection

- Ray Intersection
  - Sphere
  - Triangle
  - Box
  - Scene

- Ray Intersection Acceleration
  - Bounding volumes
  - Uniform grids
  - Octrees
  - BSP trees
Octree

• Construct adaptive grid over scene
  ◦ Recursively subdivide box-shaped cells into 8 octants
  ◦ Index primitives by overlaps with cells

Generally fewer cells
Octree

- Trace rays through neighbor cells
  - Fewer cells

Trade-off fewer cells for more expensive traversal
Octree

- Or, check rays versus octree boxes hierarchically
  - Computing octree boxes while descending tree
  - Sort eight boxes front-to-back at each level
  - Check primitives/children inside box
Ray Intersection

- Ray Intersection
  - Sphere
  - Triangle
  - Box
  - Scene

- Ray Intersection Acceleration
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  - Octrees
  - BSP trees
Binary Space Partition (BSP) Tree

• Recursively partition space by planes
  ○ BSP tree nodes store partition plane and set of polygons lying on that partition plane
  ○ Every part of every polygon lies on a partition plane
Binary Space Partition (BSP) Tree

- Traverse nodes of BSP tree front-to-back
  - Visit halfspace (child node) containing $P_0$
  - Intersect polygons lying on partition plane
  - Visit halfspace (other child node) not containing $P_0$
R3Intersection
ComputeBSPIntersection(R3Ray *ray, BspNode *node, double min_t, double max_t)
{
   // Compute parametric value of ray-plane intersection
   t = ray parameter for intersection with split plane of node
   if (t < min_t) || (t < max_t)) return no_intersection;

   // Compute side of partition plane that contains ray start point
   int side = (SignedDistance(node->plane, ray.Start()) < 0) ? 0 : 1;
   intersection1 = ComputeBSPIntersection(ray, node->child[side], min_t, t);
   if (intersection1 is a hit) return intersection1;
   intersection2 = ComputePolygonsIntersection(ray, node->polygons);
   if (intersection2 is a hit) return intersection2;
   intersection3 = ComputeBSPIntersection(ray, node->child[1-side], t, max_t);
   return intersection 3;
}
Other Accelerations

- Screen space coherence – check > 1 ray at once
  - Beam tracing
  - Pencil tracing
  - Cone tracing

- Memory coherence
  - Large scenes

- Parallelism
  - Ray casting is “embarrassingly parallelizable”
  - Assignment 3a (raytracer) runs program per-pixel

- etc.
Acceleration

- Intersection acceleration techniques are important
  - Bounding volume hierarchies
  - Spatial partitions

- General concepts
  - Sort objects spatially
  - Make trivial rejections quick
  - Perform checks hierarchically
  - Utilize coherence when possible

Expected time is sub-linear in number of primitives
Summary

- Writing a simple ray casting renderer is easy
  - Generate rays
  - Intersection tests
  - Lighting calculations

R2Image *RayCast(R3Scene *scene, int width, int height)
{
    R2Image *image = new R2Image(width, height);
    for (int i = 0; i < width; i++) {
        for (int j = 0; j < height; j++) {
            R3Ray ray = ConstructRayThroughPixel(scene->camera, i, j);
            R3Rgb radiance = ComputeRadiance(scene, &ray);
            image->SetPixel(i, j, radiance);
        }
    }
    return image;
}
Heckbert’s Business Card Ray Tracer

- typedef struct{double x,y,z}vec;vec U,black,amb={.02,.02,.02};
- struct sphere{ vec cen,color; double rad, kd, ks, kt, kl, ir}*s,*best,sph[]={0.,.6,.5,1.,.1,.1,.9,.05,.2,.85,0.,1.7,-1.8,-.5,1.,5.,2.1,.7,.3,0.,.05,1.2,1.8,-.5,.1,.8,.8,1.,.3,.7,0.,0.,1.2,3.,-6.15,1.,8.1,.7,0.,0.,0.,6.15,-3.,-3.,12.,.8,1.,1.5,0.,0.,0.,5.15};
- double u,b,tmin,sqrt(),tan();
- double vdot(A,B)vec A ,B;{return A.x*B.x+A.y*B.y+A.z*B.z;}
- vec vcomb(a,A,B)double a;vec A,B;{B.x+=a*A.x;B.y+=a*A.y;B.z+=a*A.z; return B;}
- vec vunit(A)vec A;{return vcomb(1./sqrt( vdot(A,A)),A,black);}
- struct sphere*intersect(P,D)vec P,D;{best=0;tmin=1e30;s= sph+5;while(s-->sph)b=vdot(D,U=vcomb(-1.,P,s->cen)),u=b*b-vdot(U,U)+s->rad*s->rad,u=u>0?sqrt(u):1e31,u=b-u>1e-7?b-u:b+u,tmin=u>=1e-7&&u<tmin?best=s,u: tmin;return best;}
- vec trace(level,P,D)vec P,D;{double d,eta,e;vec N,color;
- struct sphere*s,*l;if(!level--)return black;if(s=intersect(P,D));else return amb;color=amb;eta=s->ir;d= -vdot(D,N=vunit(vcomb(-1.,P=vcomb(tmin,D,P),s->cen ))));if(d<0)N=vunit(vcomb(-1.,N,black)),eta=1/eta,d= -d;l=sph+5;while(l-->sph)if((e=l->kl*vdot(N,U=vunit(vcomb(-1.,P,l->cen))))>0&&intersect(P,U)==l)color=vcomb(e ,l->color,color);U=s->color;color.x*=U.x;color.y*=U.y;color.z *=U.z;e=1-eta* eta*(1-d*d);return vcomb(s->kt,e>0?trace(level,P,vcomb(eta,D,vcomb(eta*d-sqrt (e),N,black))):black,vcomb(s->ks,trace(level,P,vcomb(2*d,N,D))),vcomb(s->kd, color,vcomb (s->kl,U,black))));}
- main(){printf("%d %d\n",32,32);while(yx<32*32) U.x=yx%32-32/2,U.z=32/2-yx++/32,U.y=32/2/tan(25/114.5915590261),U=vcomb(255., trace(3,black,vunit(U)),black),printf("%.0f %.0f %.0f\n",U);}//minray!
Next Time is Illumination!

Without Illumination

With Illumination