Hierarchical Modeling

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Reading

Required:

- Angel, sections 8.1 – 8.6, 8.8 (online handout)

Optional:

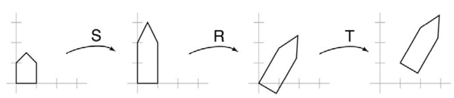
- *OpenGL Programming Guide*, chapter 3

Symbols and instances

Most graphics APIs support a few geometric **primitives**:

- spheres   gluSphere(   )
- cubes
- cylinders

These symbols are **instanced** using an **instance transformation**.



Q: What is the matrix for the instance transformation above?

$M \neq SRT$

$M = TRS$

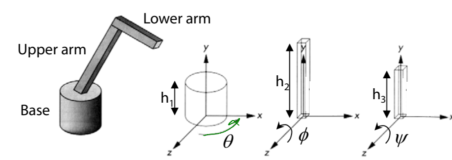
3D Example: A robot arm

Consider this robot arm with 3 degrees of freedom:

- Base rotates about its vertical axis by θ
- Upper arm rotates in its *xy*-plane by ϕ
- Lower arm rotates in its *xy*-plane by ψ

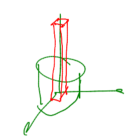
$R_x(\theta), R_y(\theta), R_z(\theta)$

$T(x, y, z)$



[Angel, 2011]

(Note that the angles are set to zero in the figure; i.e., the parts are shown in their "default" positions.)



Q: What matrix do we use to transform the base?

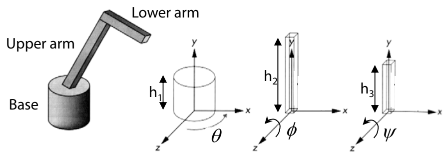
Q: What matrix for the upper arm? $R_z(\phi)\, T(0, h_1, 0)$

Q: What matrix for the lower arm?

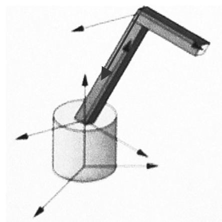
$R_y(\theta)\, T(0, h_1, 0)\, R_z(\phi)\, T(0, h_2, 0)\, R_z(\psi)$
(base) upper arm ... lower arm

3D Example: A robot arm

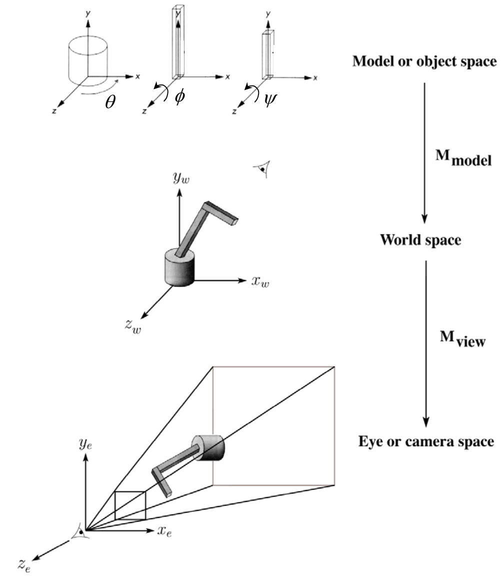
An alternative interpretation is that we are taking the original coordinate frames…



…and translating and rotating them into place:



From parts to model to viewer



Robot arm implementation

The robot arm can be displayed by keeping a global matrix and computing it at each step:

```
Matrix M, M_model, M_view;

main()
{
    . . .
    M_view = compute_view_transform();
    robot_arm();
    . . .
}

robot_arm()
{
    M_model = R_y(theta);
    M = M_view*M_model;
    base();
    M_model = R_y(theta)*T(0,h1,0)*R_z(phi);
    M = M_view*M_model;
    upper_arm();
    M_model = R_y(theta)*T(0,h1,0)
                  *R_z(phi)*T(0,h2,0)*R_z(psi);
    M = M_view*M_model;
    lower_arm();
}
```

Do the matrix computations seem wasteful?

Robot arm implementation, better

Instead of recalculating the global matrix each time, we can just update it *in place* by concatenating matrices on the right:

```
Matrix M_modelview;

main()
{
    . . .
    M_modelview = compute_view_transform();
    robot_arm();
    . . .
}

robot_arm()
{
    M_modelview *= R_y(theta);
    base();
    M_modelview *= T(0,h1,0)*R_z(phi);
    upper_arm();
    M_modelview *= T(0,h2,0)*R_z(psi);
    lower_arm();
}
```

Robot arm implementation, OpenGL

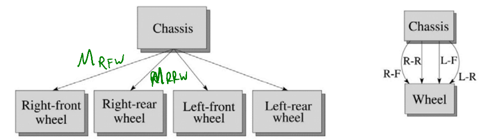
OpenGL maintains a global state matrix called the **model-view matrix**, which is updated by concatenating matrices on the ***right***.

```
main()
{
    . . .
    glMatrixMode( GL_MODELVIEW );
    Matrix M = compute_view_xform();
    glLoadMatrixf( M );
    robot_arm();
    . . .
}

robot_arm()
{
    glRotatef( theta, 0.0, 1.0, 0.0 );
    base();
    glTranslatef( 0.0, h1, 0.0 );
    glRotatef( phi, 0.0, 0.0, 1.0 );
    lower_arm();
    glTranslatef( 0.0, h2, 0.0 );
    glRotatef( psi, 0.0, 0.0, 1.0 );
    upper_arm();
}
```

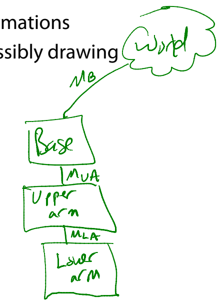

Hierarchical modeling

Hierarchical models can be composed of instances using trees or DAGs:

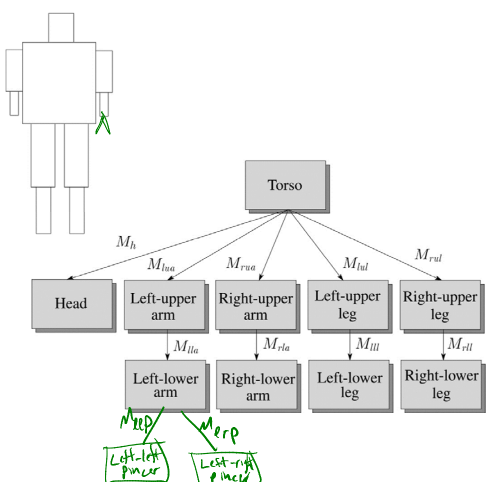


- edges contain geometric transformations
- nodes contain geometry (and possibly drawing attributes)

How might we draw the tree for the robot arm?



A complex example: human figure



Q: What's the most sensible way to traverse this tree?

Depth first

Human figure implementation, OpenGL

```
figure()
{
    torso();
    glPushMatrix();
        glTranslate( ... );
        glRotate( ... );
        head();
    glPopMatrix();
    glPushMatrix();
        glTranslate( ... );
        glRotate( ... );
        left_upper_arm();
        glPushMatrix();
            glTranslate( ... );
            glRotate( ... );
            left_lower_arm();
        glPopMatrix();
    glPopMatrix();
    . . .
}
```

Animation

The above examples are called **articulated models**:

- rigid parts
- connected by joints

They can be animated by specifying the joint angles (or other display parameters) as functions of time.

Key-frame animation

The most common method for character animation in production is **key-frame animation**.

- Each joint specified at various **key frames** (not necessarily the same as other joints)
- System does interpolation or **in-betweening**

Doing this well requires:

- A way of smoothly interpolating key frames: **splines**
- A good interactive system
- A lot of skill on the part of the animator