Parametric surfaces

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Reading

Optional reading:

- Angel and Shreiner readings for “Parametric Curves” lecture, with emphasis on 10.1.2, 10.1.3, 10.1.5, 10.6.2, 10.7.3, 10.9.4.
- Marschner and Shirley, 2.5.

Further reading

Mathematical surface representations

- **Explicit**  \( z = f(x, y) \) (a.k.a., a “height field”)
  - what if the curve isn’t a function, like a sphere?

- **Implicit**  \( g(x, y, z) = 0 \)

- **Parametric**  \( S(u, v) = (x(u, v), y(u, v), z(u, v)) \)
  - For the sphere:
    \[
    x(u, v) = r \cos(2\pi v) \sin(\pi u) \\
    y(u, v) = r \sin(2\pi v) \sin(\pi u) \\
    z(u, v) = r \cos(\pi u)
    \]

As with curves, we’ll focus on parametric surfaces.
Given: A curve $C(v)$ in the $xy$-plane:

$$
C(v) = \begin{bmatrix}
C_x(v) \\
C_y(v) \\
0 \\
\hat{I}
\end{bmatrix}
$$

Let $R_y(\theta)$ be a rotation about the $y$-axis.

Find: A surface $S(u,v)$ which is $C(v)$ rotated about the $y$-axis, where $u,v \in [0, 1]$.

Solution: $R_y(2\pi u) C(v)$
General sweep surfaces

The **surface of revolution** is a special case of a **swept surface**.

Idea: Trace out surface $S(u, v)$ by moving a **profile curve** $C(u)$ along a **trajectory curve** $T(v)$.

More specifically:

- Suppose that $C(u)$ lies in an $(x_c, y_c)$ coordinate system with origin $O_c$.
- For every point along $T(v)$, lay $C(u)$ so that $O_c$ coincides with $T(v)$. 
Orientation

The big issue:

- How to orient $C(u)$ as it moves along $T(v)$?

Here are two options:

1. **Fixed** (or **static**): Just translate $O_c$ along $T(v)$.

2. Moving. Use the **Frenet frame** of $T(v)$.
   - Allows smoothly varying orientation.
   - Permits surfaces of revolution, for example.
Frenet frames

Motivation: Given a curve $T(v)$, we want to attach a smoothly varying coordinate system.

To get a 3D coordinate system, we need 3 independent direction vectors.

- **Tangent:** $t(v) = \text{normalize}[T'(v)]$
- **Binormal:** $b(v) = \text{normalize}[T'(v) \times T''(v)]$
- **Normal:** $n(v) = b(v) \times t(v)$

As we move along $T(v)$, the Frenet frame $(t, b, n)$ varies smoothly.
**Frenet swept surfaces**

Orient the profile curve $C(u)$ using the Frenet frame of the trajectory $T(v)$:

- Put $C(u)$ in the **normal plane**.
- Place $O_c$ on $T(v)$.
- Align $x_c$ for $C(u)$ with $b$.
- Align $y'_c$ for $C(u)$ with $-n$.

If $T(v)$ is a circle, you get a surface of revolution exactly!
Degenerate frames

Let’s look back at where we computed the coordinate frames from curve derivatives:

Where might these frames be ambiguous or undetermined?
Variations

Several variations are possible:

- Scale $C(u)$ as it moves, possibly using length of $T(v)$ as a scale factor.
- Morph $C(u)$ into some other curve $\tilde{C}(u)$ as it moves along $T(v)$.
- ...
Given a grid of control points $V_{ij}$, forming a control net, construct a surface $S(u, v)$ by:

- treating rows of $V$ (the matrix consisting of the $V_{ij}$) as control points for curves $V_0(u), \ldots, V_n(u)$.
- treating $V_0(u), \ldots, V_n(u)$ as control points for a curve parameterized by $v$. 

Tensor product Bézier surfaces
Tensor product Bézier surfaces, cont.

Let’s walk through the steps:

Which control points are always interpolated by the surface?
Polynomial form of Bézier surfaces

Recall that cubic Bézier curves can be written in terms of the Bernstein polynomials:

\[ Q(u) = \sum_{i=0}^{n} V_i b_i(u) \]

A tensor product Bézier surface can be written as:

\[ S(u, v) = \sum_{i=0}^{n} \sum_{j=0}^{n} V_{ij} b_i(u) b_j(v) \]

In the previous slide, we constructed curves along \( u \), and then along \( v \). This corresponds to re-grouping the terms like so:

\[ S(u, v) = \sum_{j=0}^{n} \left( \sum_{i=0}^{n} V_{ij} b_i(u) \right) b_j(v) \]

But, we could have constructed them along \( v \), then \( u \):

\[ S(u, v) = \sum_{i=0}^{n} \left( \sum_{j=0}^{n} V_{ij} b_j(v) \right) b_i(u) \]
Tensor product B-spline surfaces

As with spline curves, we can piece together a sequence of Bézier surfaces to make a spline surface. If we enforce $C^2$ continuity and local control, we get B-spline curves:

- treat rows of $B$ as control points to generate Bézier control points in $u$.
- treat Bézier control points in $u$ as B-spline control points in $v$.
- treat B-spline control points in $v$ to generate Bézier control points in $u$. 
Tensor product B-spline surfaces, cont.

Which B-spline control points are always interpolated by the surface?
Tensor product B-splines, cont.

Another example:
NURBS surfaces

Uniform B-spline surfaces are a special case of NURBS surfaces.
Trimmed NURBS surfaces

Sometimes, we want to have control over which parts of a NURBS surface get drawn.

For example:

We can do this by trimming the $u$-$v$ domain.

- Define a closed curve in the $u$-$v$ domain (a trim curve)
- Do not draw the surface points inside of this curve.

It’s really hard to maintain continuity in these regions, especially while animating.
Summary

What to take home:

- How to construct swept surfaces from a profile and trajectory curve:
  - with a fixed frame
  - with a Frenet frame
- How to construct tensor product Bézier surfaces
- How to construct tensor product B-spline surfaces