

Surfaces

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Reading

Required:

- ♦ Watt, 2.1.4, 3.4-3.5.

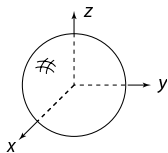
Optional

- ♦ Watt, 3.6.
- ♦ Bartels, Beatty, and Barsky. *An Introduction to Splines for use in Computer Graphics and Geometric Modeling*, 1987.

2

Mathematical surface representations

- ♦ Explicit $z=f(x,y)$ (a.k.a., a “height field”)
 - what if the surface isn't a function?



- ♦ Implicit $g(x,y,z) = 0$

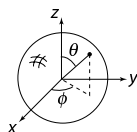
- ♦ Parametric $(x(u,v),y(u,v),z(u,v))$

- For the sphere:

$$x(u,v) = r \cos 2\pi v \sin \pi u$$

$$y(u,v) = r \sin 2\pi v \sin \pi u$$

$$z(u,v) = r \cos \pi u$$



We'll focus mostly on parametric surfaces.

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Surfaces of revolution

Idea: rotate a 2D **profile curve** around an axis.

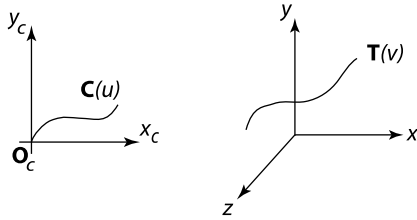
What kinds of shapes can you model this way?

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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 $T(v)$.

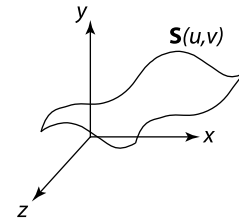
Orientation

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.** Reorient as you move along, based on orientation of $T(v)$

- Allows smoothly varying orientation.
- Permits surfaces of revolution, for example.

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 $T(v)$

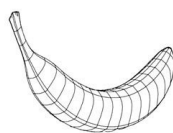
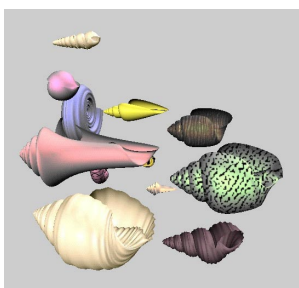
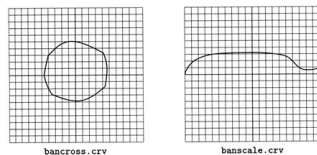
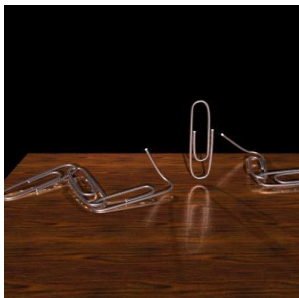
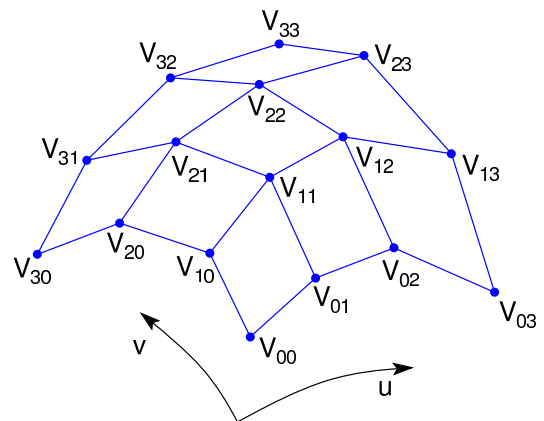


Figure 3.8: Banana example. A banana is represented by an affine transformation surface. The cross section is scaled, translated along z from -1 to 1 , and rotated around the y axis. □

Tensor product Bézier surfaces

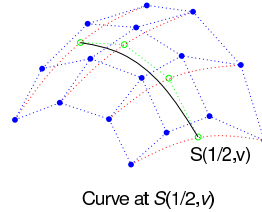
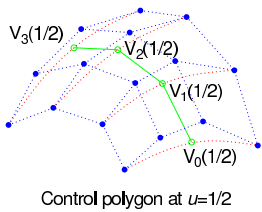
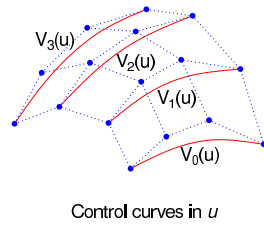
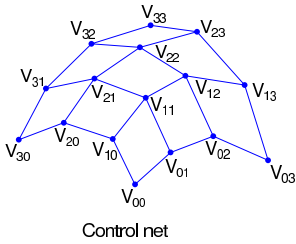


Given a grid of control points V_{ij} forming a **control net**, construct a surface $S(u,v)$ by:

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

Tensor product Bézier surfaces, cont.

Let's walk through the steps:



Which control points are interpolated by the surface?

Matrix form of Bézier surfaces

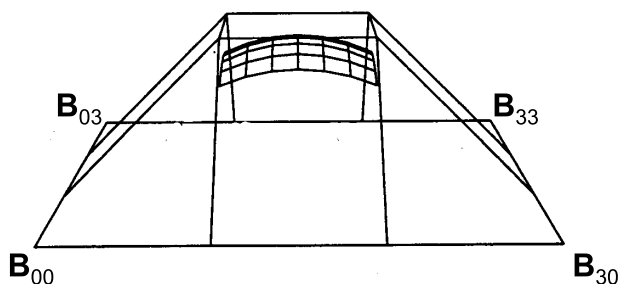
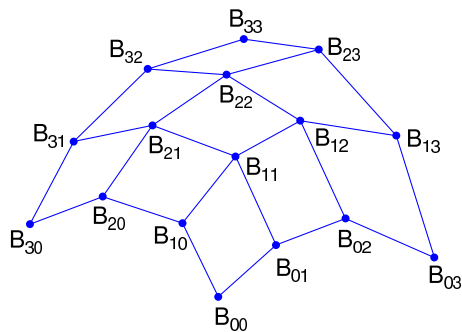
Tensor product surfaces can be written explicitly:

$$\mathbf{S}(u, v) = \sum_{i=0}^n \sum_{j=0}^n \mathbf{v}_{ij} P_i^n(u) P_j^n(v)$$

$$= \begin{bmatrix} u^3 & u^2 & u & 1 \end{bmatrix} M_{\text{Bézier}} \mathbf{V} M_{\text{Bézier}}^T \begin{bmatrix} v^3 \\ v^2 \\ v \\ 1 \end{bmatrix}$$

Tensor product B-spline surfaces

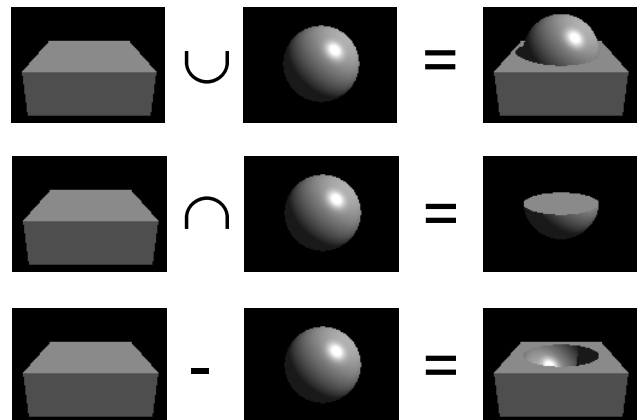
As with spline curves, we can piece together a sequence of Bézier surfaces to make a spline surface. If we enforce C^2 continuity and local control, we get B-spline surfaces:



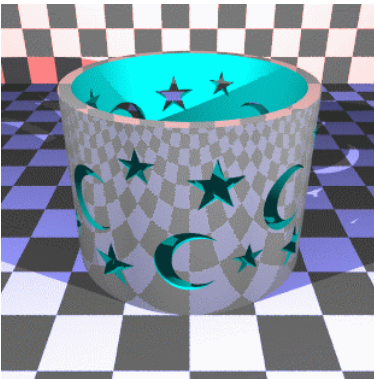
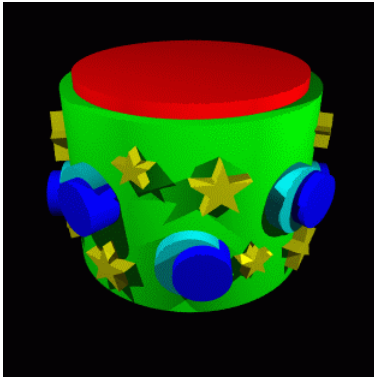
Constructive solid geometry

Simple shapes can be combined together to make more complex shapes. This process is called **constructive solid geometry (CSG)**

- ♦ glue pieces together
- ♦ saw parts off, drill holes



CSG, cont.



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CSG with implicit functions

CSG operations are easier to implement with implicit functions.

Let $f(x,y,z)$ and $g(x,y,z)$ be implicit representations of two shapes where

- ♦ $f(x,y,z) < 0$ if (x,y,z) is inside the shape
- ♦ $f(x,y,z) > 0$ if (x,y,z) is outside the shape
- ♦ $f(x,y,z) = 0$ if (x,y,z) is on the surface

h = **union** of f and g

- ♦ $h(x,y,z) = \min(f(x,y,z), g(x,y,z))$

h = **intersection** of f and g

- ♦ $h(x,y,z) =$

$h = f - g$

- ♦ $h(x,y,z) =$

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Summary

What to take home:

- ♦ How to construct swept surfaces from a profile and trajectory curve
- ♦ How to construct tensor product Bézier surfaces
- ♦ CSG with implicit functions

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