Geometry and Transformations

Digital Image Synthesis

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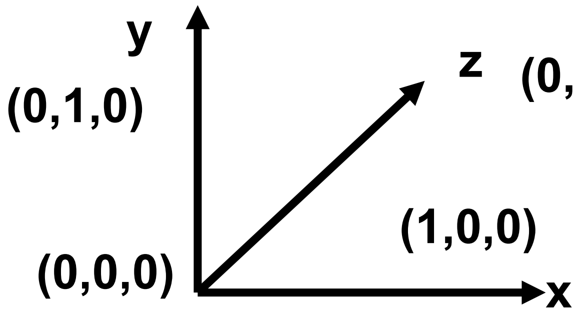
with slides by Pat Hanrahan

Geometric classes

- Representation and operations for the basic mathematical constructs like points, vectors and rays.
- Actual scene geometry such as triangles and spheres are defined in the "Shapes" chapter.
- core/geometry.* and core/transform.*
- Purposes of learning this chapter
  - Get used to the style of learning by tracing source code
  - Get familiar to the basic geometry utilities because you will use them intensively later on

Coordinate system

- Points, vectors and normals are represented with three floating-point coordinate values: *x, y, z* defined under a coordinate system.
- A coordinate system is defined by an origin p_o and a frame (linearly independent vectors v_i).
- A vector $v = s_1 v_1 + \ldots + s_n v_n$ represents a direction, while a point $p = p_o + s_1 v_1 + \ldots + s_n v_n$ represents a position. They are not freely interchangeable.
- pbrt uses left-handed coordinate system.



world space

Vectors

```
class Vector {
  public:
     <Vector Public Methods>
     float x, y, z;
}
```

no need to use selector (getX) and mutator (setX)
because the design gains nothing and adds bulk to its usage

Provided operations: **`Vector u, v; float a;`**

```
v+u, v-u, v+=u, v-=u
-v
(v==u)
a*v, v*=a, v/a, v/=a
a=v[i], v[i]=a
```

Dot and cross product

```
Dot(v, u)
AbsDot(v, u)
```

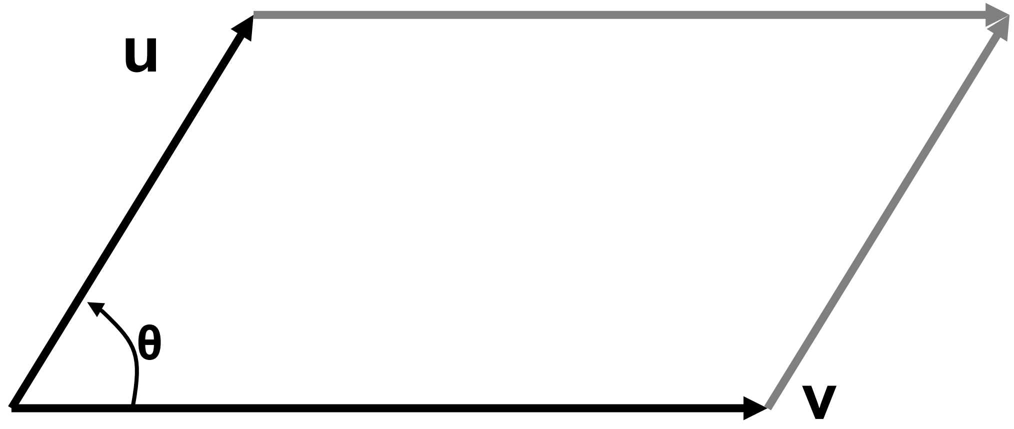
$$v \cdot u = \|v\|\|u\|\cos\theta$$

```
Cross(v, u)
```

$$\|v \times u\| = \|v\|\|u\|\sin\theta$$

Vectors v, u, v×u form a frame

$$(v \times u)_x = v_y u_z - v_z u_y$$
$$(v \times u)_y = v_z u_x - v_x u_z$$
$$(v \times u)_z = v_x u_y - v_y u_z$$



Normalization

`a=LengthSquared(v)`

`a=Length(v)`

`u=Normalize(v)` *return a vector, does not normalize in place*

Coordinate system from a vector

Construct a local coordinate system from a vector.

```
inline void CoordinateSystem(const Vector &v1,
                       Vector *v2, Vector *v3)
{
  if (fabsf(v1.x) > fabsf(v1.y)) {
    float invLen = 1.f/sqrtf(v1.x*v1.x + v1.z*v1.z);
    *v2 = Vector(-v1.z * invLen, 0.f, v1.x * invLen);
  }
  else {
    float invLen = 1.f/sqrtf(v1.y*v1.y + v1.z*v1.z);
    *v2 = Vector(0.f, v1.z * invLen, -v1.y * invLen);
  }
  *v3 = Cross(v1, *v2);
}
```

Points

Points are different from vectors; given a coordinate system (p_0,v_1,v_2,v_3), a point p and a vector v with the same (x,y,z) essentially means

$$p=(x,y,z,1)[v_1\ v_2\ v_3\ p_0]^T$$

$$v=(x,y,z,0)[v_1\ v_2\ v_3\ p_0]^T$$

```
explicit Vector(const Point &p);
```

You have to convert a point to a vector explicitly (i.e. you know what you are doing).

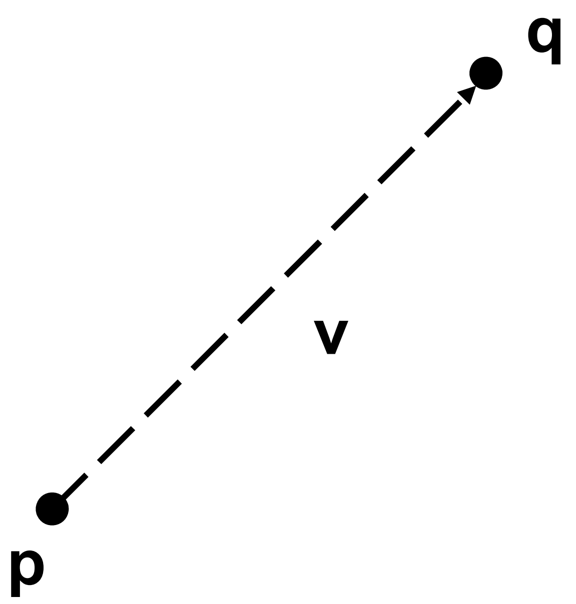
☒ `Vector v=p;`

☑ `Vector v=Vector(p);`

Operations for points

```
Vector v; Point p, q, r; float a;

q=p+v;
q=p-v;
v=q-p;
```



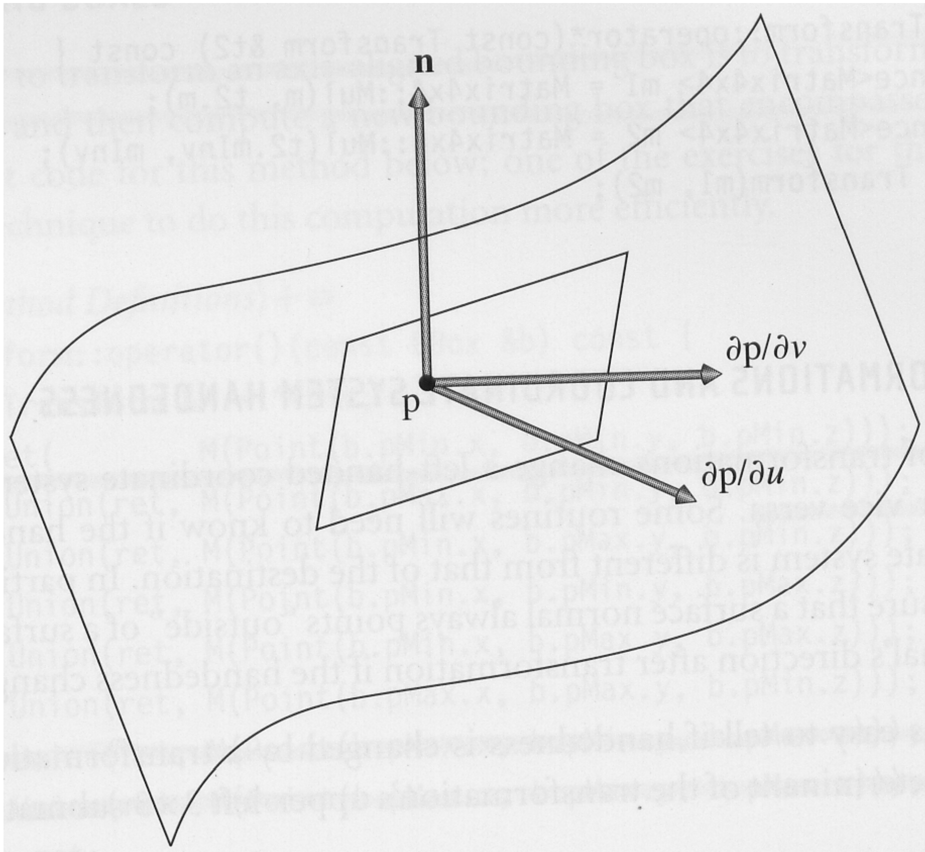

```
r=p+q;
a*p; p/a;
```

(This is only for the operation $\alpha p+\beta q$*.)*

```
Distance(p,q);
DistanceSquared(p,q);
```

Normals

- A *surface normal* (or just *normal*) is a vector that is perpendicular to a surface at a particular position.



Normals

- Different than vectors in some situations, particularly when applying transformations.
- Implementation similar to **`Vector`**, but a normal cannot be added to a point and one cannot take the cross product of two normals.
- **`Normal`** is not necessarily normalized.
- Only explicit conversion between **`Vector`** and **`Normal`**.

Rays

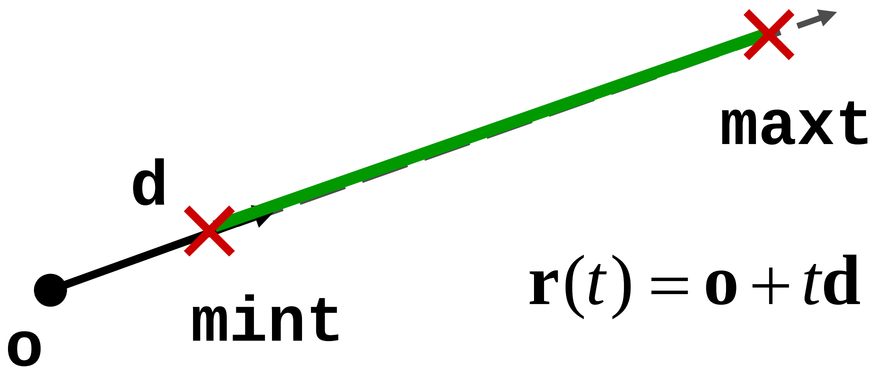
```
class Ray {
public:
   <Ray Public Methods>
   Point o;
   Vector d;
   mutable float mint, maxt;
   float time;
};
```

(They may be changed even if **Ray** is **const**. This ensures that o and d are not modified, but mint and maxt can be.)

Initialized as **RAY_EPSILON** to avoid self intersection.

(for motion blur)

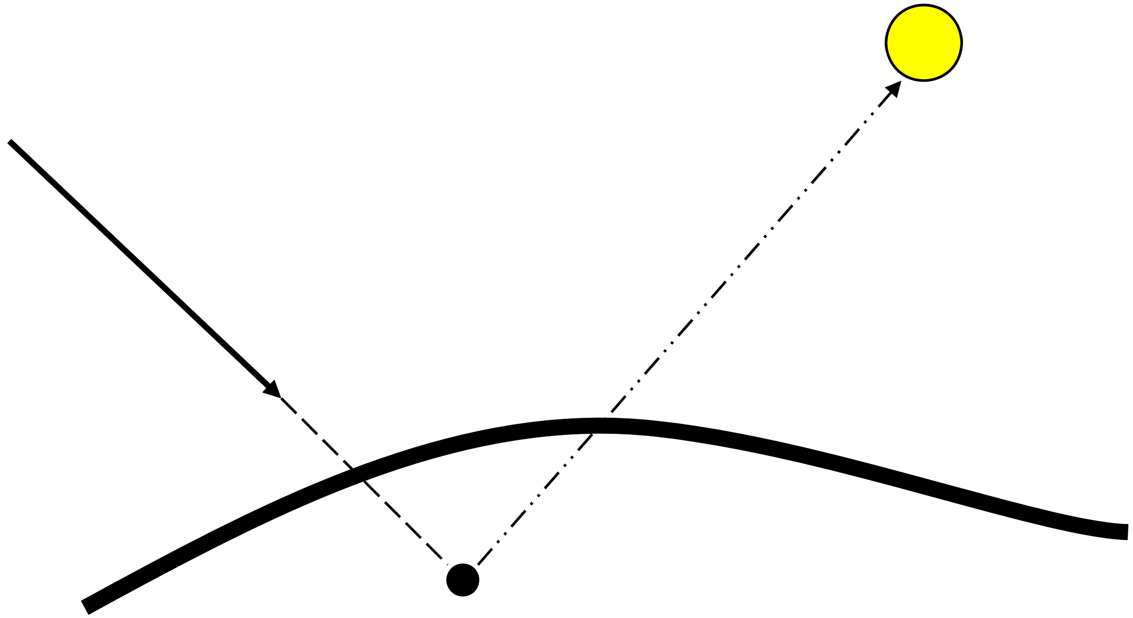
```
Ray r(o, d);
Point p=r(t);
```



$$\mathbf{r}(t)=\mathbf{o}+t\mathbf{d} \qquad 0\le t\le\infty$$

Rays

```
Ray(): mint(RAY_EPSILON), maxt(INFINITY),
  time(0.f) {}
```

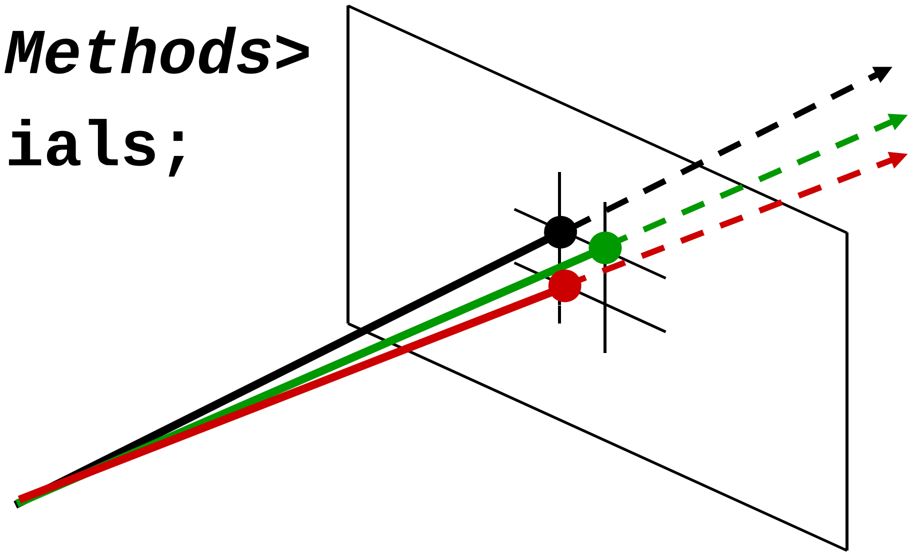


The reason why we need epsilon. Unfortunately, there is not a universal epsilon that works for all scenes.

Ray differentials

- Subclass of **`Ray`** with two auxiliary rays. Used to estimate the projected area for a small part of a scene and for antialiasing in **Texture**.

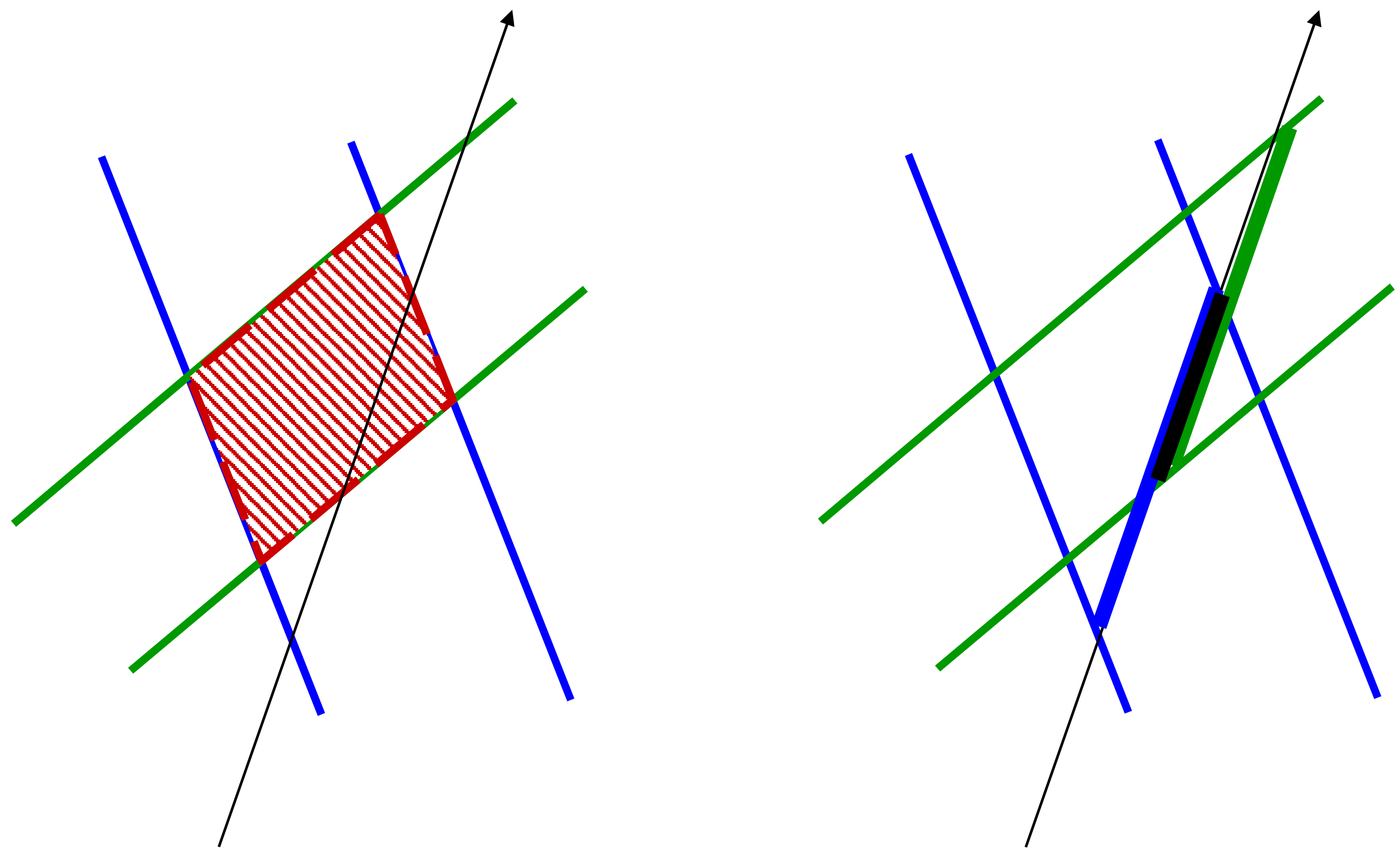
```
class RayDifferential : public Ray {
public:
  <RayDifferential Methods>
  bool hasDifferentials;
  Ray rx, ry;
};
```



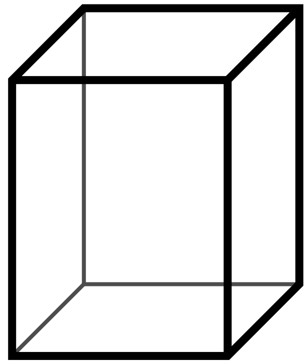
Bounding boxes

- To avoid intersection test inside a volume if the ray doesn't hit the *bounding volume*.
- Benefits depends on the expense of testing volume *v.s.* objects inside and the tightness of the bounding volume.
- Popular bounding volume, sphere, axis-aligned bounding box (AABB), oriented bounding box (OBB) and slab.

Bounding volume (slab)



Bounding boxes



```
class BBox {
public:
  <BBox Public Methods>
  Point pMin, pMax;
}
```

two options of storing

```
Point p,q; BBox b; float delta; bool s;
b = BBox(p,q)   // no order for p, q
b = Union(b,p)
b = Union(b,b2)
b = b.Expand(delta)
s = b.Overlaps(b2)
s = b.Inside(p)
Volume(b)
b.MaximumExtent()
b.BoundingSphere(c, r)
```

`b.MaximumExtent()` *which axis is the longest; for building kd-tree*

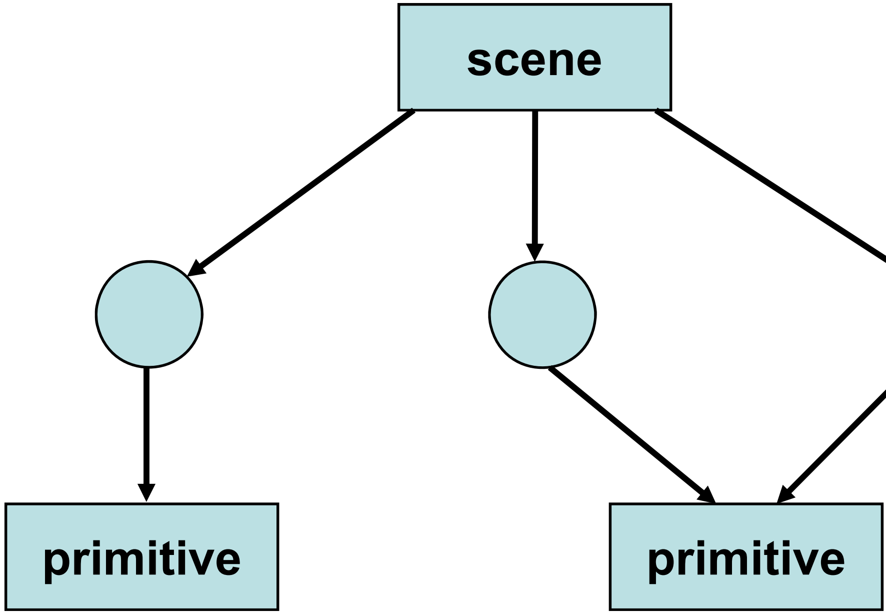
`b.BoundingSphere(c, r)` *for generating samples*

Transformations

- p'=T(p);   v'=T(v)
- Only supports transforms with the following properties:
  - Linear: $T(a\mathbf{v}+b\mathbf{u})=aT(\mathbf{v})+bT(\mathbf{u})$
  - Continuous: T maps the neighbors of p to ones of p'
  - Ont-to-one and invertible: T maps p to single p' and T^{-1} exists
- Represented with a 4x4 matrix; homogeneous coordinates are used implicitly
- Can be applied to points, vectors and normals
- Simplify implementations (e.g. cameras and shapes)

Transformations

- More convenient, instancing



scene graph

Transformations

```
class Transform {
...
private:
  Reference<Matrix4x4> m, mInv;
}
```

save space, but can't be modified after construction
Usually not a problem because transforms are pre-specified in the scene file and won't be changed during rendering.

```
Transform() {m = mInv = new Matrix4x4; }
Transform(float mat[4][4]);
Transform(const Reference<Matrix4x4> &mat);
Transform(const Reference<Matrix4x4> &mat,
          const Reference<Matrix4x4> &minv);
```

A better way to initialize

Transformations

- `Translate(Vector(dx,dy,dz))`
- `Scale(sx,sy,sz)`
- `RotateX(a)`

$$T(dx,dy,dz)=\begin{pmatrix}1&0&0&dx\\0&1&0&dy\\0&0&1&dz\\0&0&0&1\end{pmatrix}$$

$$R_x(\theta)=\begin{pmatrix}1&0&0&0\\0&\cos\theta&-\sin\theta&0\\0&\sin\theta&\cos\theta&0\\0&0&0&1\end{pmatrix}$$

$$S(sx,sy,sz)=\begin{pmatrix}sx&0&0&0\\0&sy&0&0\\0&0&sz&0\\0&0&0&1\end{pmatrix}$$

$$R_x(\theta)^{-1}=R_x(\theta)^{\mathrm{T}}$$

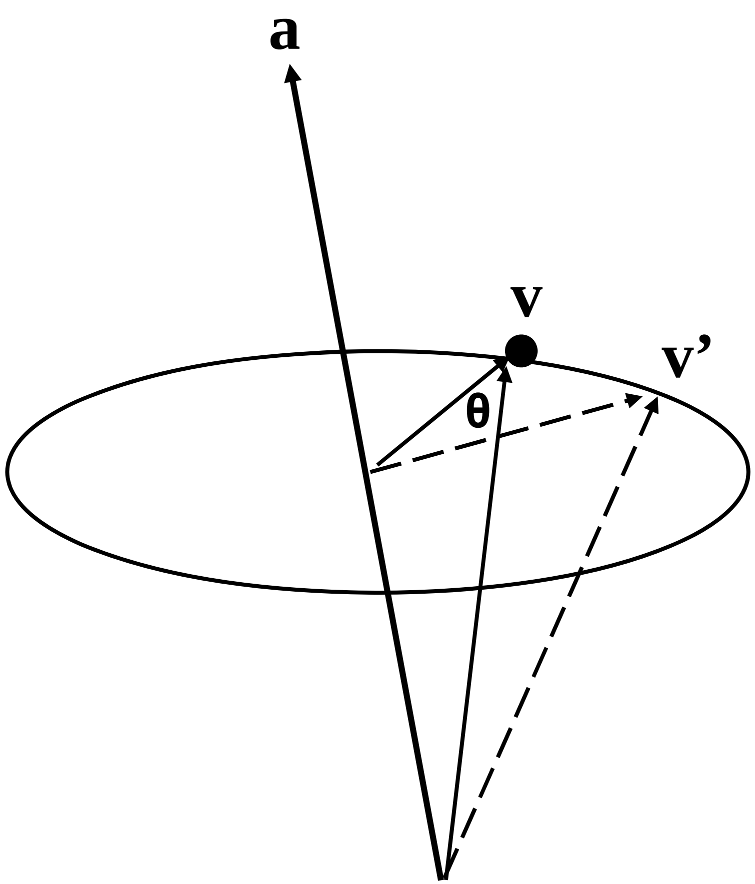
because R is orthogonal

Example for creating common transforms

```
Transform Translate(const Vector &delta) {
  Matrix4x4 *m, *minv;
  m = new Matrix4x4(1, 0, 0, delta.x,
                    0, 1, 0, delta.y,
                    0, 0, 1, delta.z,
                    0, 0, 0,       1);
  minv = new Matrix4x4(1, 0, 0, -delta.x,
                       0, 1, 0, -delta.y,
                       0, 0, 1, -delta.z,
                       0, 0, 0,        1);
  return Transform(m, minv);
}
```

Rotation around an arbitrary axis

- Rotate(theta, axis) *axis is normalized*



Rotation around an arbitrary axis

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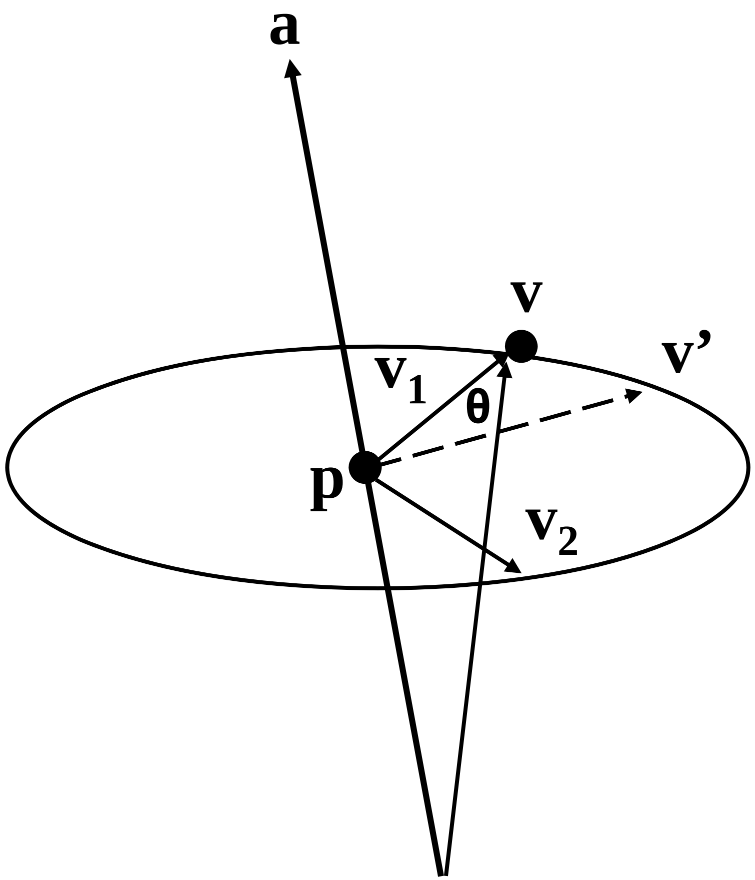


$$\mathbf{p} = \mathbf{a}(\mathbf{v} \cdot \mathbf{a})$$

$$\mathbf{v_1} = \mathbf{v} - \mathbf{p}$$

$$\mathbf{v}_2 = \mathbf{a} \times \mathbf{v}_1 \qquad \left|\mathbf{v}_2\right| = \left|\mathbf{v}_1\right|$$

$$\mathbf{v}' = p + \mathbf{v}_1 \cos\theta + \mathbf{v}_2 \sin\theta$$

Rotation around an arbitrary axis

- Rotate(theta, axis) *axis is normalized*

$$\mathbf{p} = \mathbf{a}(\mathbf{v} \cdot \mathbf{a})$$

$$\mathbf{v_1} = \mathbf{v} - \mathbf{p}$$

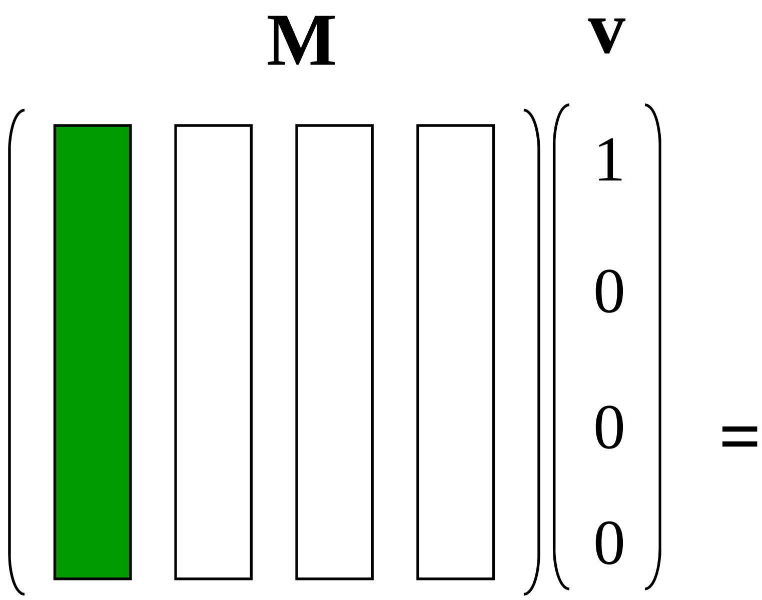
$$\mathbf{v}_2 = \mathbf{a} \times \mathbf{v}_1 \qquad |\mathbf{v}_2| = |\mathbf{v}_1|$$

$$\begin{array}{cc} \mathbf{M} & \mathbf{v} \\ \left(\quad \right) & \left(\quad \right) \end{array} = \quad \mathbf{v}' = p + \mathbf{v}_1 \cos\theta + \mathbf{v}_2 \sin\theta$$

Rotation around an arbitrary axis

```
m[0][0]=a.x*a.x  + (1.f-a.x*a.x)*c;
m[1][0]=a.x*a.y*(1.f-c) + a.z*s;
m[2][0]=a.x*a.z*(1.f-c) - a.y*s;
```

$$\mathbf{p} = \mathbf{a}(\mathbf{v}\cdot\mathbf{a})$$



$$\mathbf{v_1} = \mathbf{v} - \mathbf{p}$$

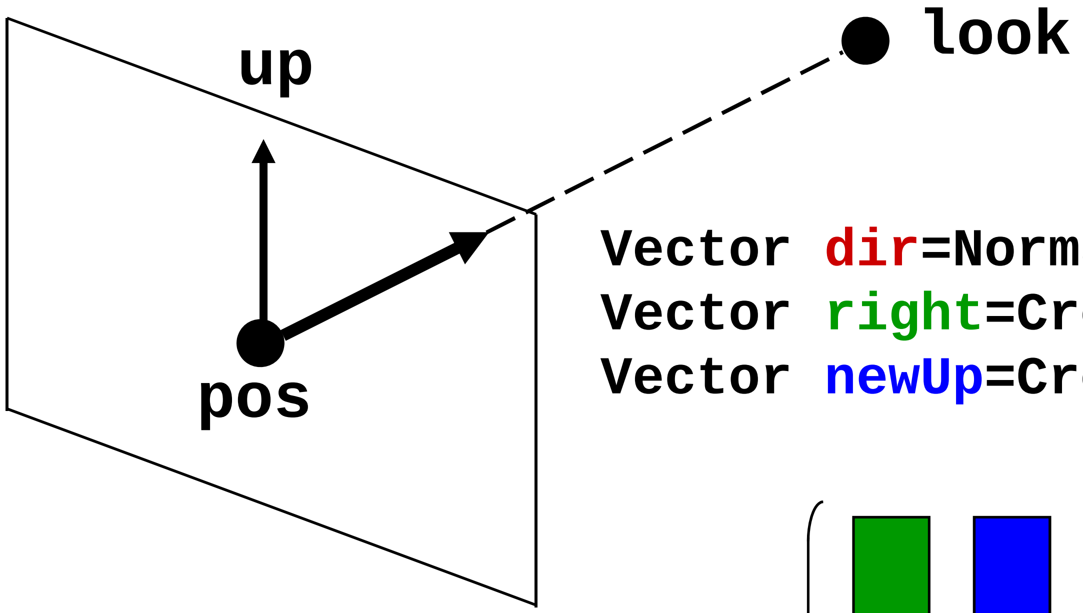
$$\mathbf{v}_2 = \mathbf{a}\times\mathbf{v}_1 \qquad |\mathbf{v}_2| = |\mathbf{v}_1|$$

$$\mathbf{v}' = p + \mathbf{v}_1\cos\theta + \mathbf{v}_2\sin\theta$$

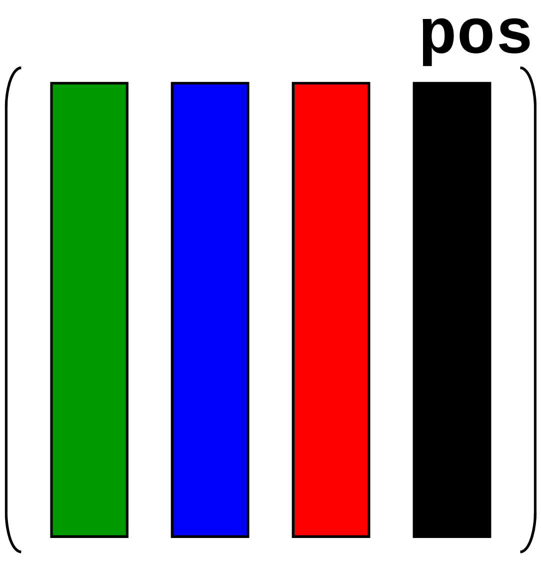
Look-at

- `LookAt(Point &pos, Point look, Vector &up)`

up is not necessarily perpendicular to dir



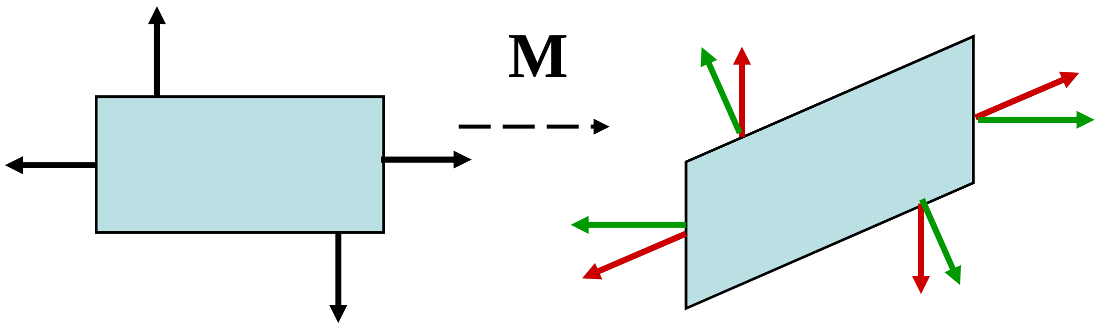

```
Vector dir=Normalize(look-pos);
Vector right=Cross(dir, Normalize(up));
Vector newUp=Cross(right,dir);
```



Applying transformations

Point: (p, 1)
Vector: (v, 0)

- **`Point`**: `q=T(p), T(p,&q)`
  use homogeneous coordinates implicitly
- **`Vector`**: `u=T(v), T(u, &v)`
- **`Normal`**: treated differently than vectors because of anisotropic transformations



$$\mathbf{n}\cdot\mathbf{t} = \mathbf{n}^{\mathrm{T}}\mathbf{t} = 0$$

$$(\mathbf{n}')^{\mathrm{T}}\mathbf{t}' = 0$$

$$(\mathbf{S}\mathbf{n})^{\mathrm{T}}\mathbf{M}\mathbf{t} = 0$$

$$\mathbf{n}^{\mathrm{T}}\mathbf{S}^{\mathrm{T}}\mathbf{M}\mathbf{t} = 0$$

$$\mathbf{S}^{\mathrm{T}}\mathbf{M} = \mathbf{I}$$

$$\boxed{\mathbf{S} = \mathbf{M}^{-\mathrm{T}}}$$

- **`Transform`** should keep its inverse
- For orthonormal matrix, $\mathbf{S}=\mathbf{M}$

Applying transformations

- **BBox**: transforms its eight corners and expand to include all eight points.

```
BBox Transform::operator()(const BBox &b) const {
  const Transform &M = *this;
  BBox ret(        M(Point(b.pMin.x, b.pMin.y, b.pMin.z)));
  ret = Union(ret,M(Point(b.pMax.x, b.pMin.y, b.pMin.z)));
  ret = Union(ret,M(Point(b.pMin.x, b.pMax.y, b.pMin.z)));
  ret = Union(ret,M(Point(b.pMin.x, b.pMin.y, b.pMax.z)));
  ret = Union(ret,M(Point(b.pMin.x, b.pMax.y, b.pMax.z)));
  ret = Union(ret,M(Point(b.pMax.x, b.pMax.y, b.pMin.z)));
  ret = Union(ret,M(Point(b.pMax.x, b.pMin.y, b.pMax.z)));
  ret = Union(ret,M(Point(b.pMax.x, b.pMax.y, b.pMax.z)));
  return ret;
}
```

Differential geometry

- **`DifferentialGeometry`**: a self-contained representation for a particular point on a surface so that all the other operations in pbrt can be executed without referring to the original shape. It contains
- Position
- Parameterization (u,v)
- Parametric derivatives (dp/du, dp/dv)
- Surface normal (derived from (dp/du)x(dp/dv))
- Derivatives of normals
- Pointer to shape