

# Parametric Surfaces

CSE 457

Winter 2015

## Reading

### Required:

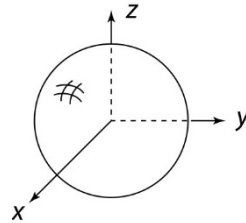
- ◆ Angel readings for “Parametric Curves” lecture, with emphasis on 10.1.2, 10.1.3, 10.1.5, 10.6.2, 10.7.3, 10.9.4.

### Optional

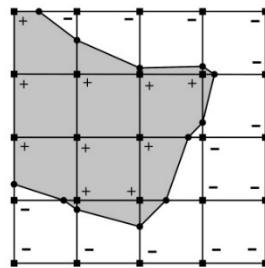
- ◆ Bartels, Beatty, and Barsky. *An Introduction to Splines for use in Computer Graphics and Geometric Modeling*, 1987.

# Mathematical surface representations

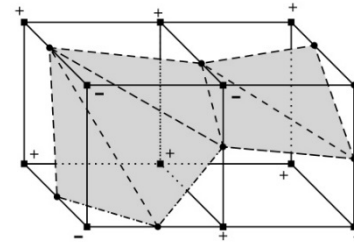
- ◆ Explicit  $z=f(x,y)$  (a.k.a., a “height field”)
  - what if the curve isn’t a function, like a sphere?



- ◆ Implicit  $g(x,y,z) = 0$



Isocontour from “marching squares”



Isocontour from “marching cubes”

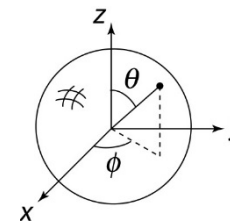
- ◆ Parametric  $S(u,v)=(x(u,v),y(u,v),z(u,v))$

- For the sphere:

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

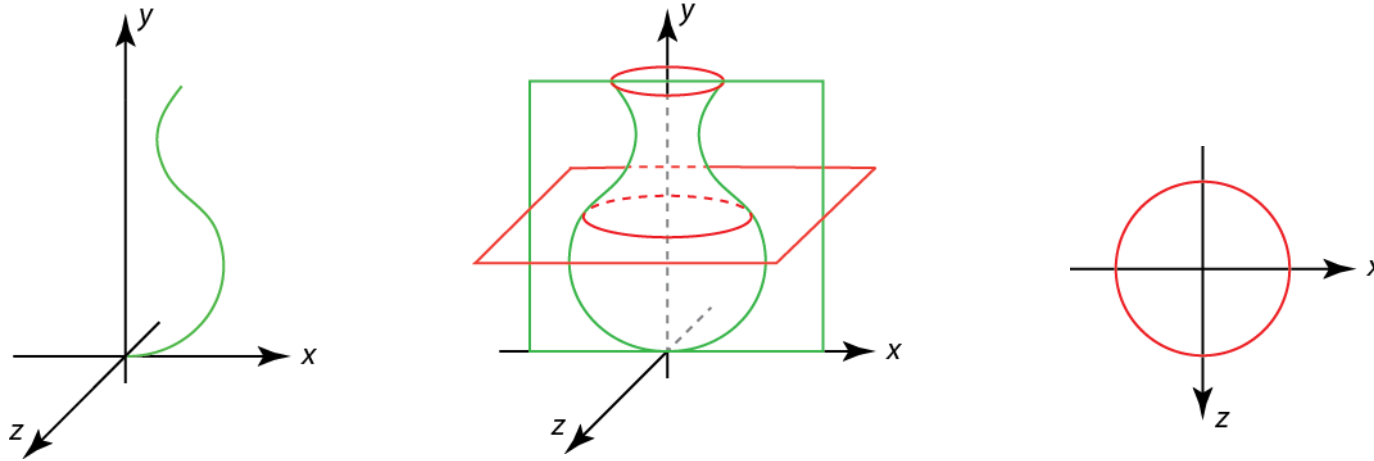
$$y(u,v) = r \sin 2\pi v \sin \pi u$$

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



As with curves, we’ll focus on parametric surfaces.

## Surfaces of revolution



**Given:** A curve  $C(u)$  in the  $xy$ -plane:

$$C(u) = \begin{bmatrix} c_x(u) \\ c_y(u) \\ 0 \\ 1 \end{bmatrix}$$

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

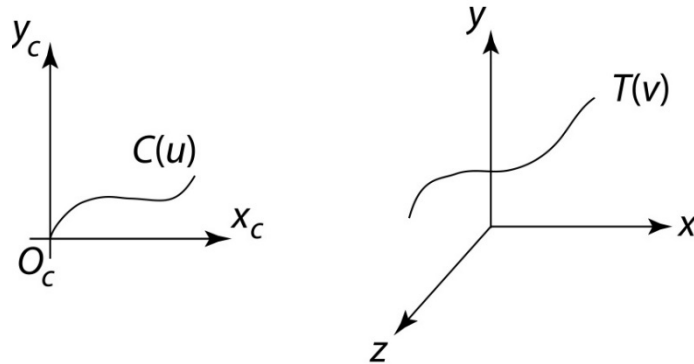
**Find:** A surface  $S(u,v)$  which is  $C(u)$  rotated about the  $y$ -axis, where  $u, v \in [0, 1]$ .

**Solution:**

## 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  $T(v)$ .

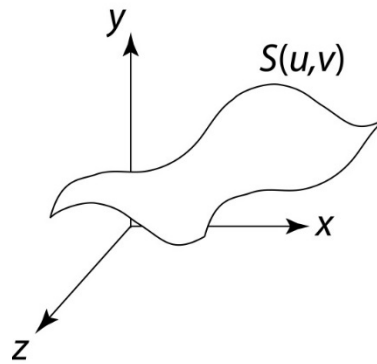
# Orientation

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  $T(v)$ .

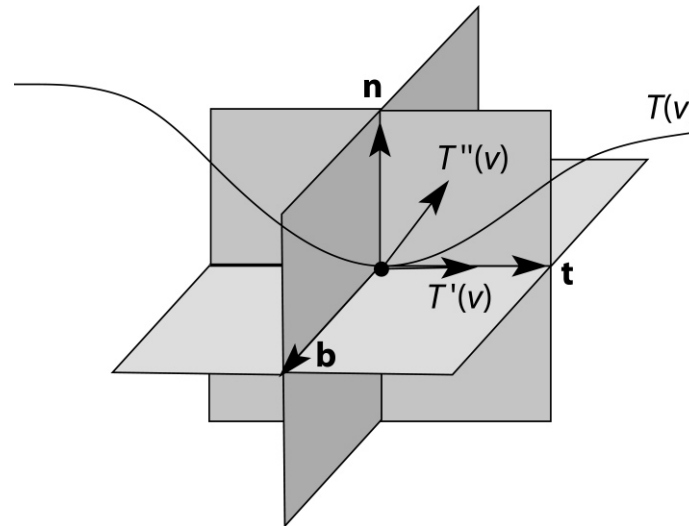


2. Moving. Use the **Frenet frame** of  $T(v)$ .

- ◆ 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:  $\mathbf{t}(v) = \text{normalize}[T'(v)]$

Binormal:  $\mathbf{b}(v) = \text{normalize}[T'(v) \times T''(v)]$

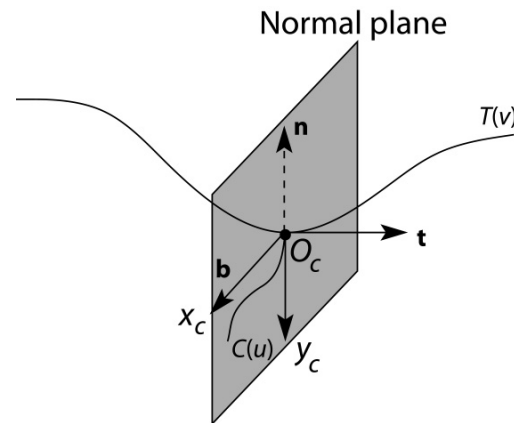
Normal:  $\mathbf{n}(v) = \mathbf{b}(v) \times \mathbf{t}(v)$

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**.

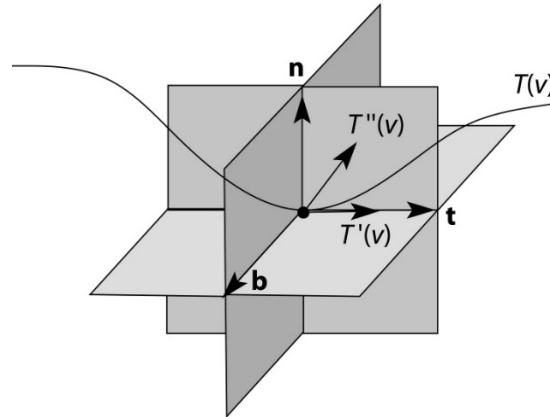


If  $T(v)$  is a circle, you get a surface of revolution exactly!



## Degenerate frames

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

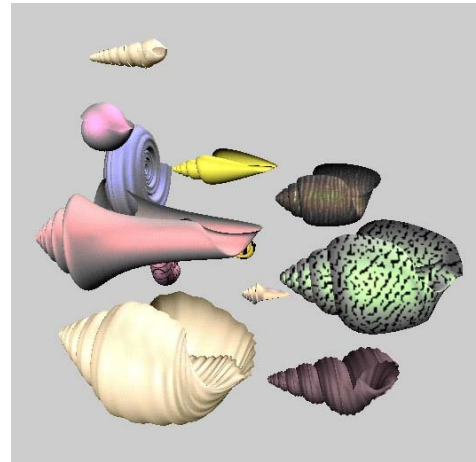
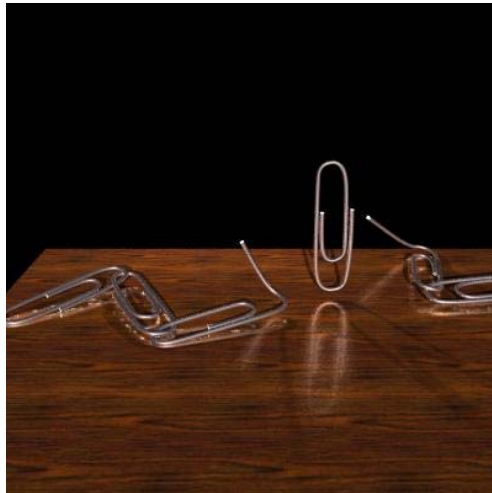


Where might these frames be ambiguous or undetermined?

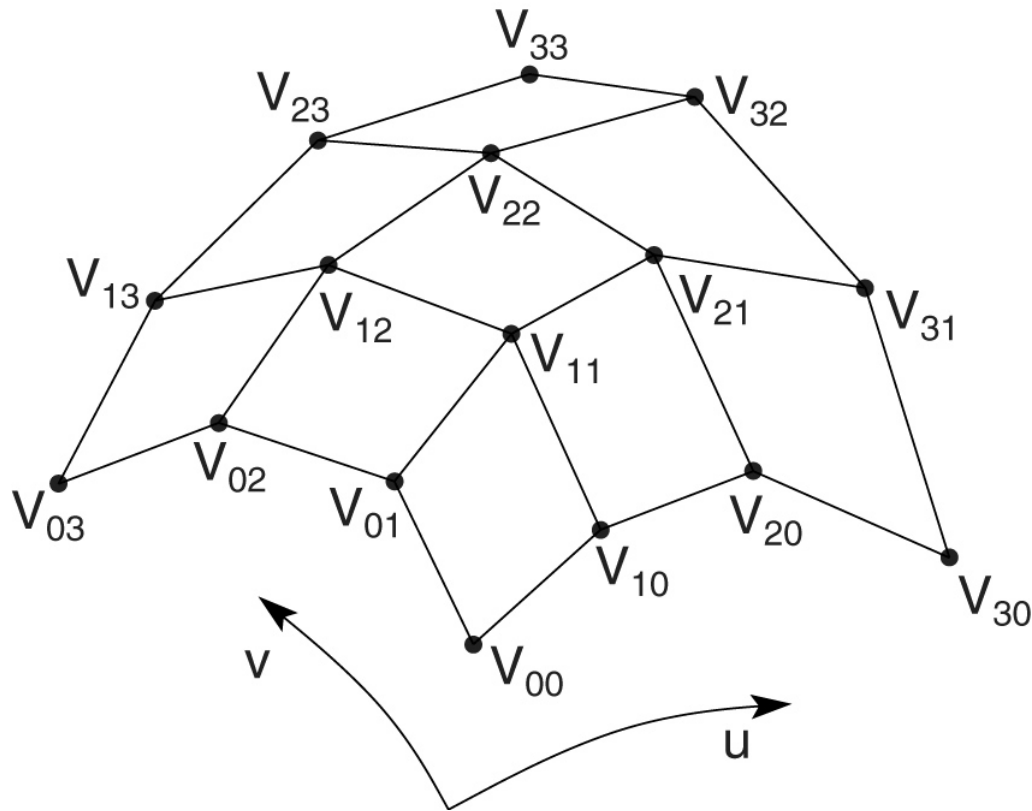
# Variations

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  $T(v)$ .
- ◆ ...



## Tensor product Bézier surfaces

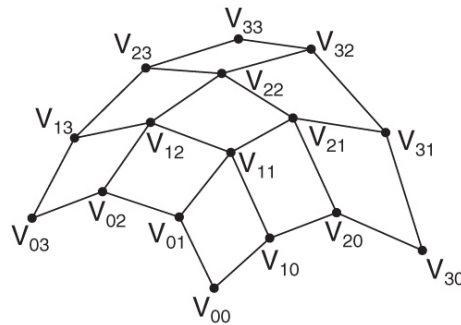


Given a grid of control points  $V_{ij}$ , forming a **control net**, construct a surface  $S(u,v)$  by:

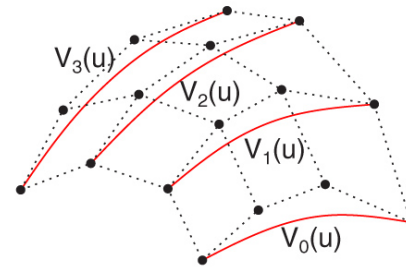
- ♦ treating rows of  $V$  (the matrix consisting of the  $V_{ij}$ ) as control points for curves  $V_0(u), \dots, V_n(u)$ .
- ♦ treating  $V_0(u), \dots, V_n(u)$  as control points for a curve parameterized by  $v$ .

# Tensor product Bézier surfaces, cont.

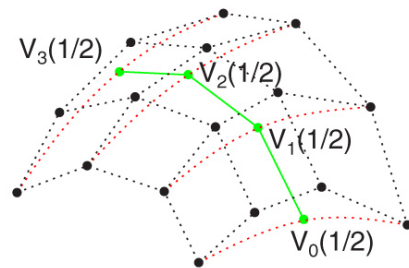
Let's walk through the steps:



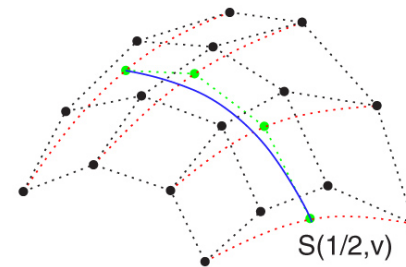
Control net



Control curves in  $u$



Control polygon at  $u=1/2$



Curve at  $S(1/2, v)$

Which control points are 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:

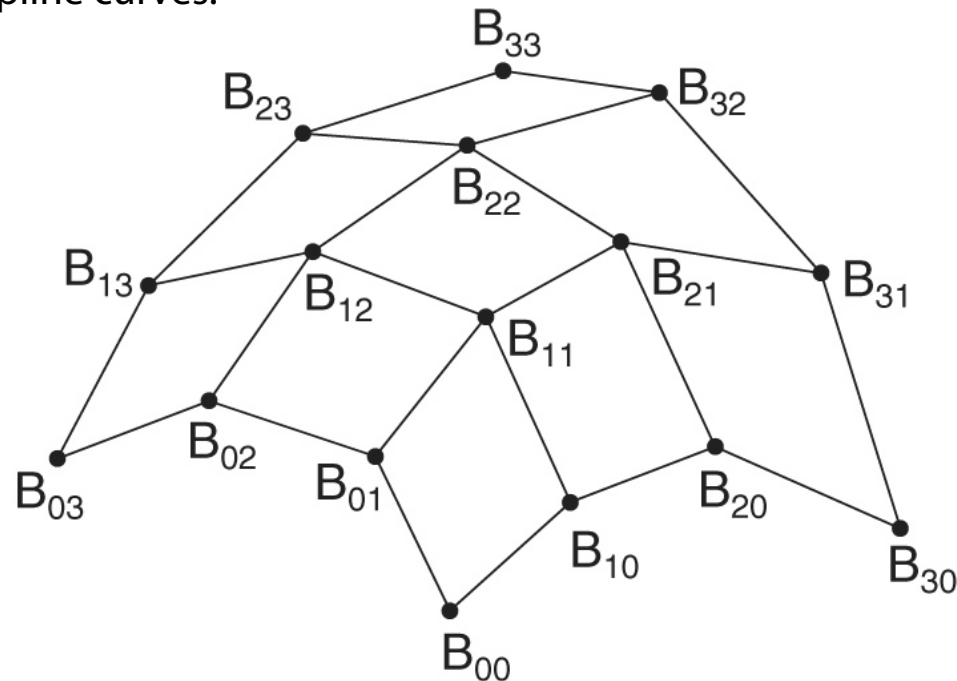
$$S(u,v) = \sum_{j=0}^n \left( \sum_{i=0}^n V_{ij} b_i(u) \right) b_j(v)$$

But, we could have constructed them along  $v$ , then  $u$ :

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

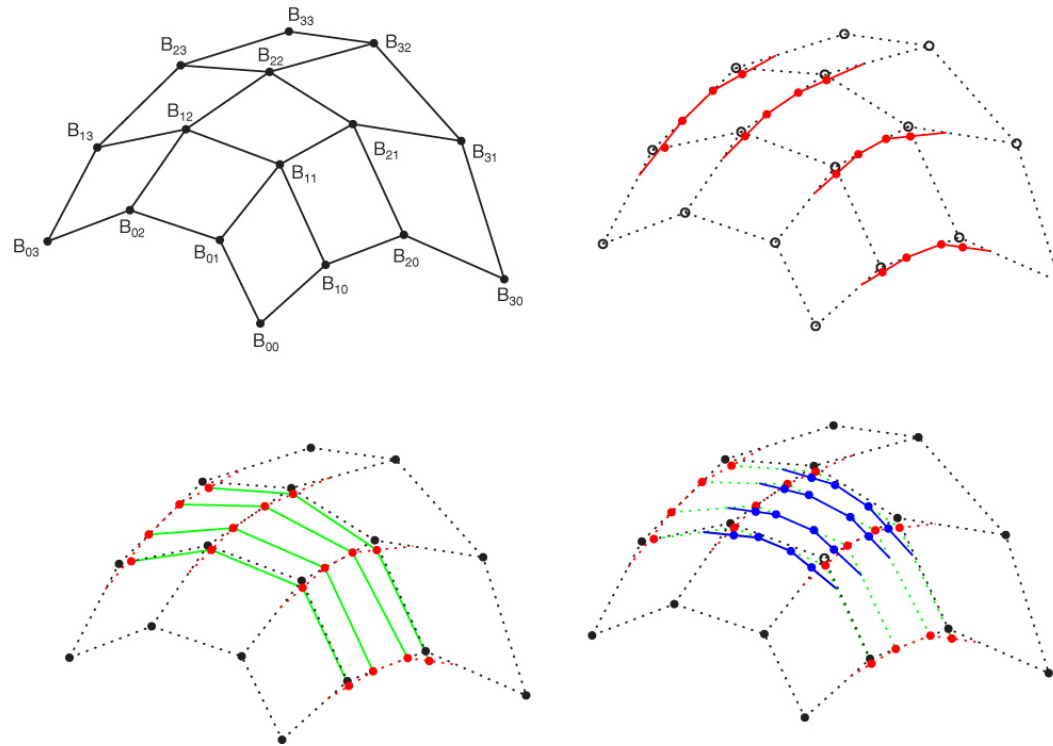
## Tensor product B-spline surfaces

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  $u$ .

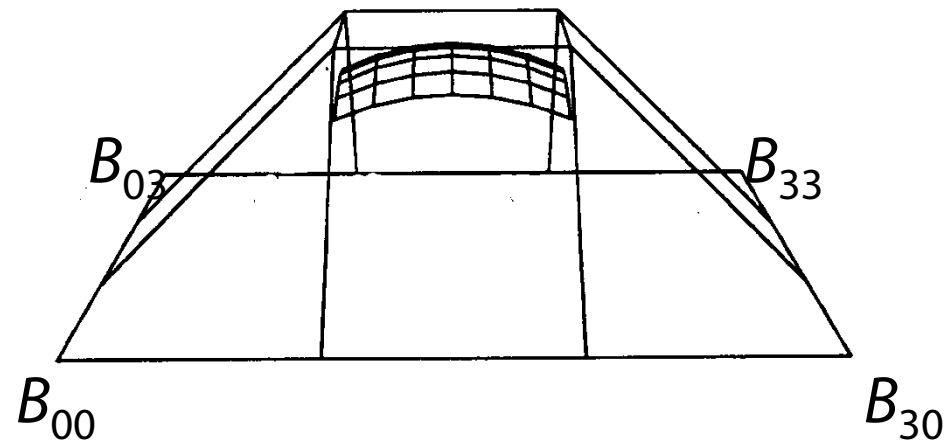
## Tensor product B-spline surfaces, cont.



Which B-spline control points are interpolated by the surface?

## Tensor product B-splines, cont.

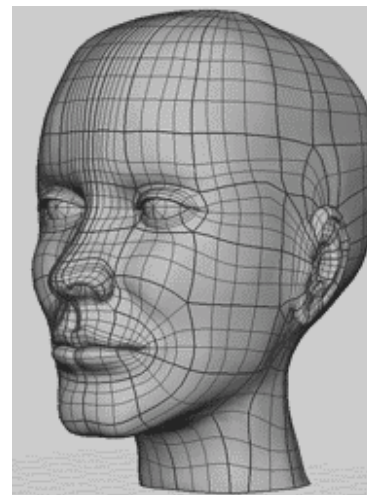
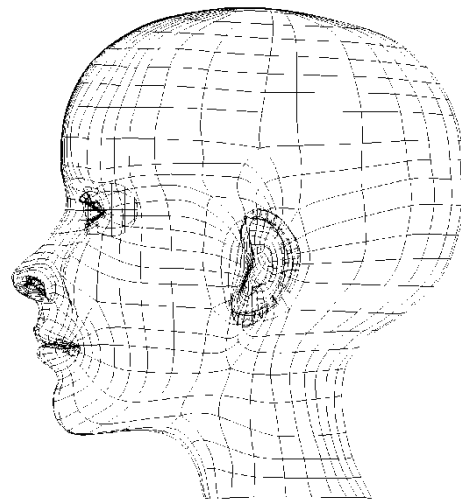
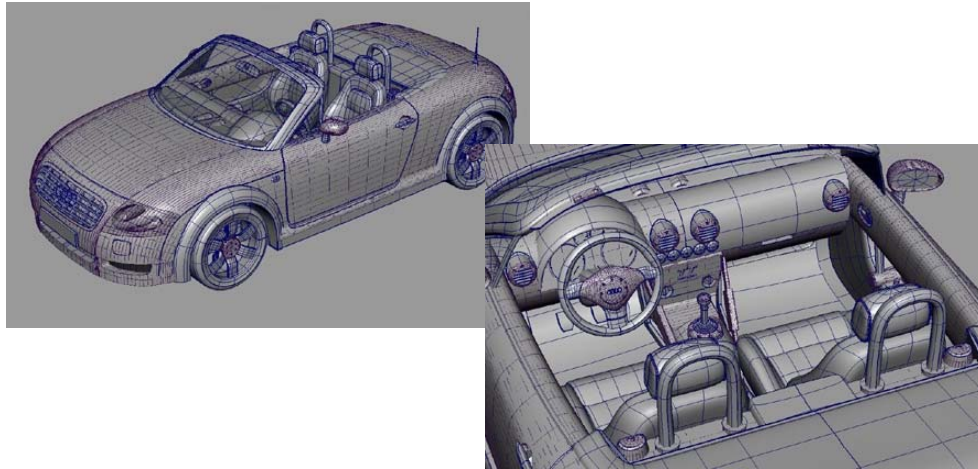
Another example:





## NURBS surfaces

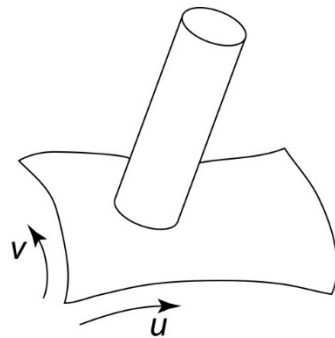
Uniform B-spline surfaces are a special case of NURBS surfaces.



## 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