Parametric surfaces

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CSE 557
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Reading

Required:

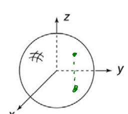
- Shirley, 2.5

Optional

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

Mathematical surface representations

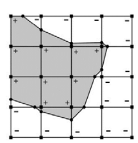
- Explicit $z=f(x,y)$ (a.k.a., a "height field")
  - what if the curve isn't a function, like a sphere?



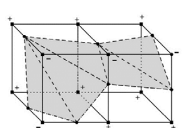
- Implicit $g(x,y,z) = 0$

$x^2+y^2+z^2=r^2$

$g(x,y,z)=x^2+y^2+z^2-r^2$



Isocontour from "marching squares"



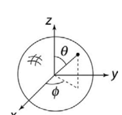
Isocontour from "marching cubes"

- Parametric $S(u,v)=(x(u,v),y(u,v),z(u,v))$
  - For the sphere:

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

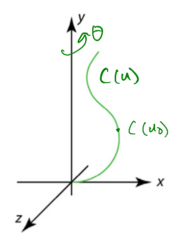
    $y(u,v) = r\sin 2\pi v \sin \pi u$

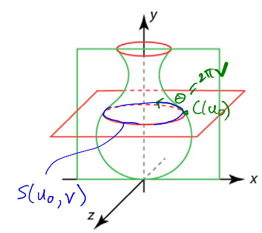
    $z(u,v) = r\cos \pi u$

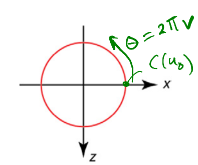


As with curves, we'll focus on parametric surfaces.

Constructing 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.

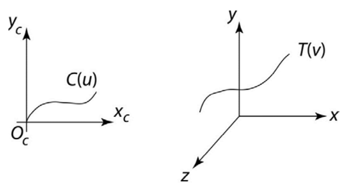
Find: A surface $S(u,v)$ which is $C(u)$ rotated about the y-axis, where $u, v \in [0, 1]$.

Solution: $S(u,v) = R_y(2\pi v)C(u)$

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 $T(v)$.

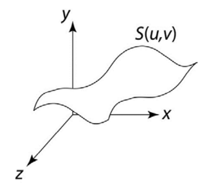
Orientation

The big issue:

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

Here are two options:

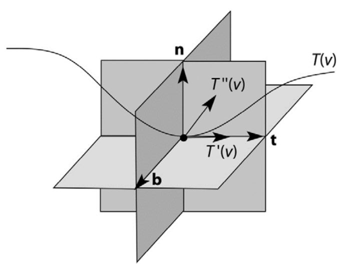
1. **Fixed** (or **static**): Just translate O_c along $T(v)$.



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.

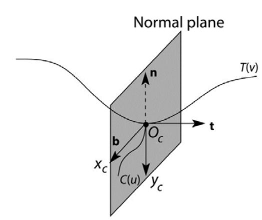
$$
\begin{aligned}
&\text{Tangent:} && \mathbf{t}(v) = \text{normalize}[T'(v)] \\
&\text{Binormal:} && \mathbf{b}(v) = \text{normalize}[T'(v) \times T''(v)] \\
&\text{Normal:} && \mathbf{n}(v) = \mathbf{b}(v) \times \mathbf{t}(v)
\end{aligned}
$$

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 $T(v)$:

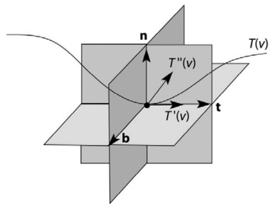
- Put $C(u)$ in the **normal plane** .
- Place O_c on $T(v)$.
- Align x_c for $C(u)$ with **b**.
- Align y_c for $C(u)$ with -**n**.



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:

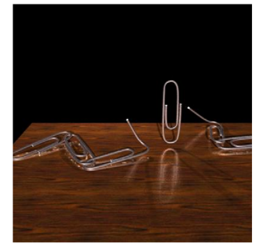


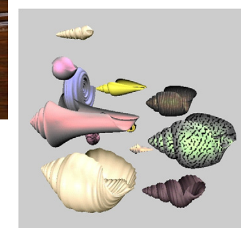
Where might these frames be ambiguous or undetermined?

Variations

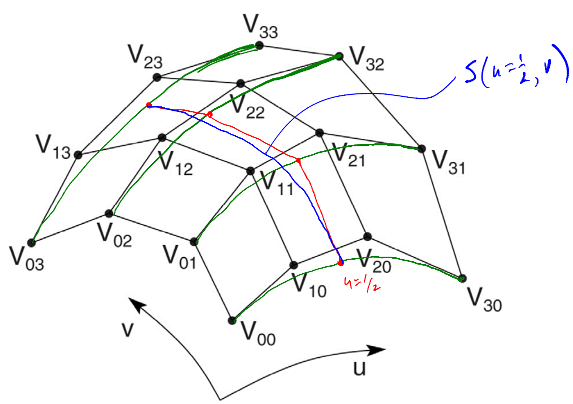
Several variations are possible:

- 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

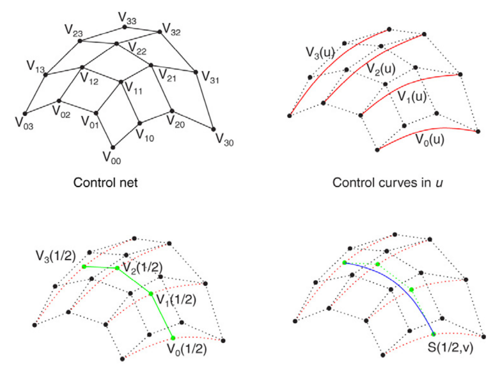


Given a grid of control points V_{ij}, forming a **control net**, construct a surface $S(u,v)$ by:

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

Tensor product Bézier surfaces, 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?

Corners

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:

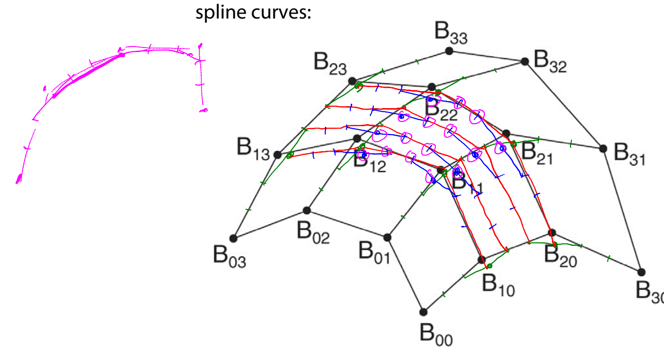
$$S(u,v) = \sum_{j=0}^{n} \left(\sum_{i=0}^{n} V_{ij} b_i(u) \right) b_j(v)$$

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

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

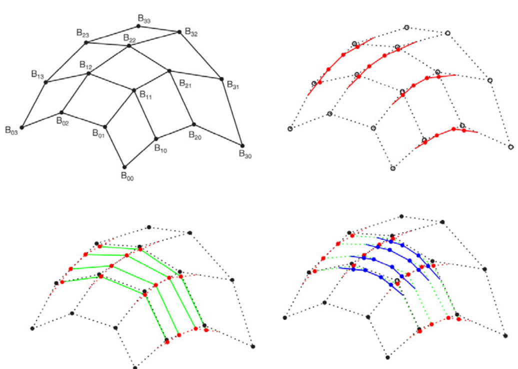
Tensor product B-spline surfaces

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.

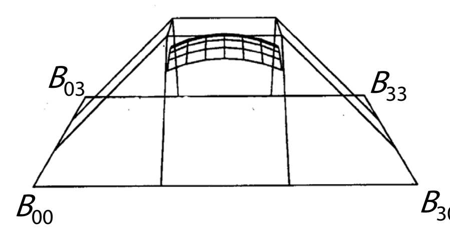


Which B-spline control points are interpolated by the surface?

None

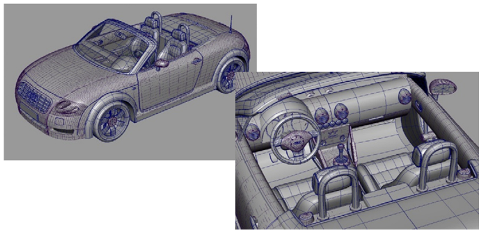
Tensor product B-splines, cont.

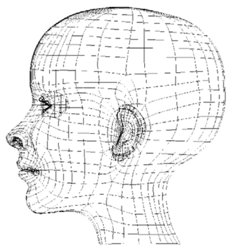
Another example:

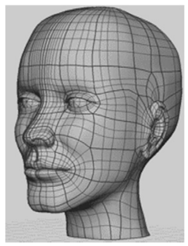


NURBS surfaces

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



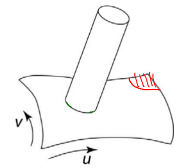


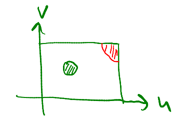


Trimmed NURBS surfaces

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.