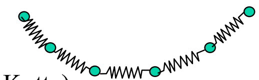
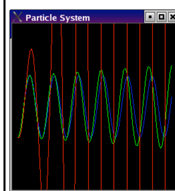
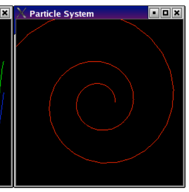
Voxels, Implicit Surfaces, & Collisions

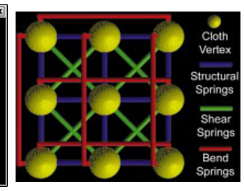
Last Time?

- Spring-Mass Systems
- Numerical Integration (Euler, Midpoint, Runge-Kutta)
- Modeling string, hair, & cloth









Today

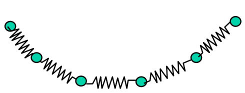
- More on Cloth!
  - Stiffness
  - Implicit Integration
- Implicit Surfaces
- Voxels
- Collisions
- Readings for Today

The Stiffness Issue

- What relative stiffness do we want for the different springs in the network?
- Cloth is barely elastic, shouldn't stretch so much!
- Inverse relationship between stiffness & Δt
- We really want constraints (not springs)
- Many numerical solutions
  - reduce Δt
  - use constraints
  - implicit integration
  - …

How would you simulate a string?

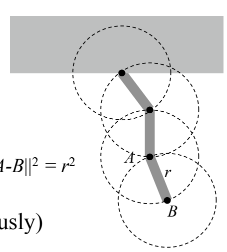
- Springs link the particles. Problems?
  - Stretch, actual length will be greater than rest length
  - Numerical oscillation



- Rigid, fixed-length bars link the particles
  - Dynamics &
  - Constraints

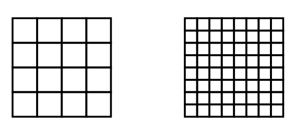
  (must be solved simultaneously)

$\|A-B\|^2 = r^2$



The Discretization Problem

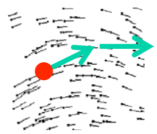
- What happens if we discretize our cloth more finely, or with a different mesh structure?



- Do we get the same behavior?
  - Usually not! It takes a lot of effort to design a scheme that does not depend on the discretization.
- Using (explicit) Euler, how many timesteps before a force propagates across the mesh?

Explicit vs. Implicit Integration

- With an explicit/forward integration scheme:
  $$\mathbf{y}_{k+1} = \mathbf{y}_k + h\,\mathbf{g}(\mathrm{y}_k)$$
  we must use a very small timestep to simulate *stable, stiff* cloth.

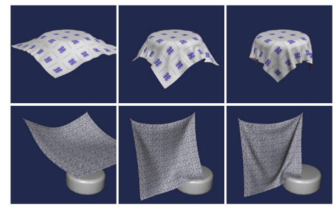


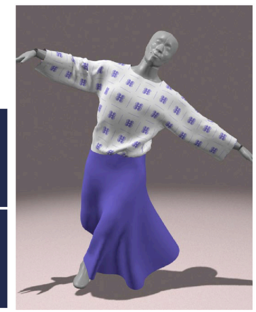
- Alternatively we can use an implicit/backwards scheme:
  $$\mathbf{y}_{k+1} = \mathbf{y}_k + h\,\mathbf{g}(\mathrm{y}_{k+1})$$
  $$\mathbf{y}_k = \mathbf{y}_{k+1} - h\,\mathbf{g}(\mathrm{y}_{k+1})$$
  Solving one step is much more expensive (Newton's Method, Conjugate Gradients, …) but overall faster than the thousands of explicit timesteps required for very stiff springs.

Questions?

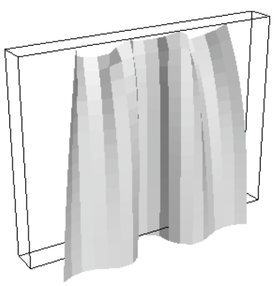
David Baraff & Andrew Witkin
Large Steps in Cloth Simulation
SIGGRAPH 1998

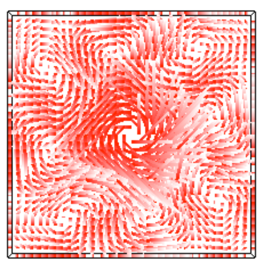
- Dynamic motion driven by animation





HW2: Cloth & Fluid Simulation





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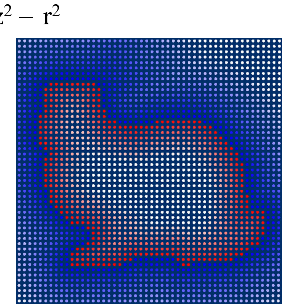
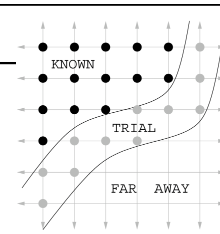
Implicit Surfaces

- For a sphere:
  $H(x,y,z) = x^2 + y^2 + z^2 - r^2$
- If $H(x,y,z) = 0$, on surface
- If $H(x,y,z) > 0$, outside surface
- If $H(x,y,z) < 0$, inside surface

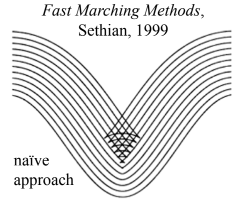


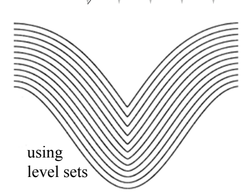
Level Sets

- Efficient method for computing signed distance field



Level Set Methods and Fast Marching Methods, Sethian, 1999

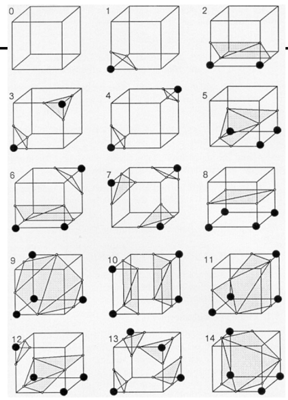




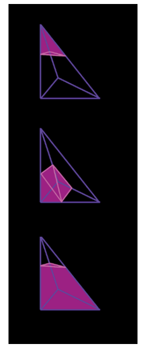
Marching Cubes

- Polygonization: extract triangle mesh from signed distance field

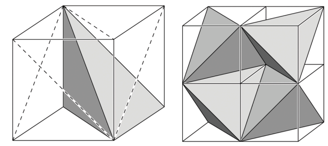
"Marching Cubes: A High Resolution 3D Surface Construction Algorithm", Lorensen and Cline, SIGGRAPH '87.



"Marching Tetrahedra"

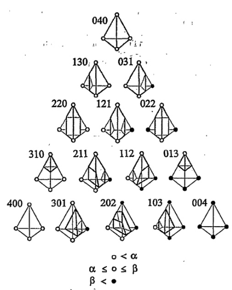


Jules Bloomenthal
"An implicit surface polygonizer"
Graphics Gems IV



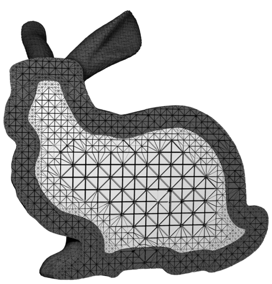
"When the Blobs Go Marching Two by Two",
Jeff Lander, Gamasutra

"Marching Tetrahedra"



"Interval volume tetrahedrization"
Visualization '97
Nielson & Sung

Similarly, we can create volumetric models:



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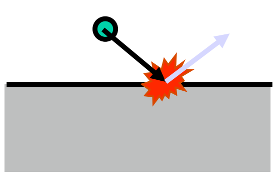
Collisions

- Detection
- Response
- Overshooting problem (when we enter the solid)



Detecting Collisions

- Easy with implicit equations of surfaces
- H(x,y,z)=0 at surface
- H(x,y,z)<0 inside surface
- So just compute H and you know that you're inside if it's negative

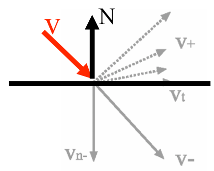
- More complex with other surface definitions

Collision Response

- tangential velocity v_t unchanged
- normal velocity v_n reflects:

$$v = v_t + v_n$$

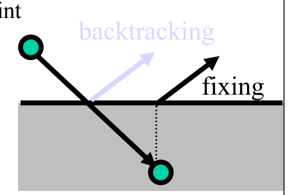
$$v \leftarrow v_t - \varepsilon v_n$$



- coefficient of restitution (1 for elastic, 0 for plastic)
- change of velocity = *-(1+ε)v*
- change of momentum *Impulse = -m(1+ε)v*

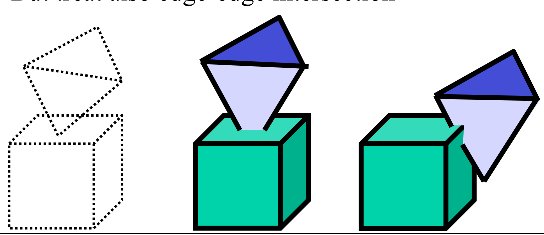
Collisions - Overshooting

- Usually, we detect collision when it's too late: we're already inside
- Solutions: back up
  - Compute intersection point
  - Compute response there
  - Advance for remaining fractional time step
- Other solution: Quick and dirty fixup
  - Just project back to object closest point



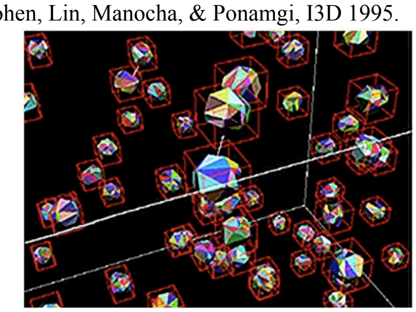
Collision Detection for Solids

- How to detect collision between 2 polyhedra?
- Need an inside/outside test
- Test if a vertex is inside the other polyhedron
- But treat also edge-edge intersection



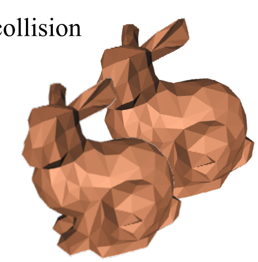
Reading for Today

- "I-COLLIDE: An Interactive and Exact Collision Detection System for Large-scaled Environments", Cohen, Lin, Manocha, & Ponamgi, I3D 1995.



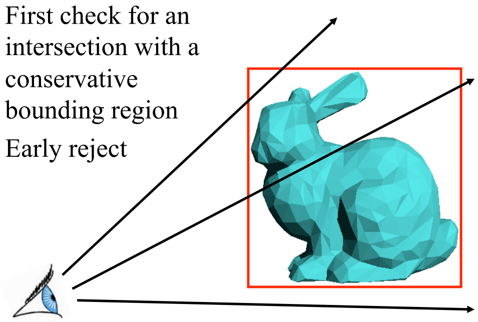
Cost of Detection?

- Test each edge with each face?
  - $O(N^2)$
- How would you detect collision between two bunnies?
  - $O(N^2)$ is too expensive!
  - Use spatial hierarchy



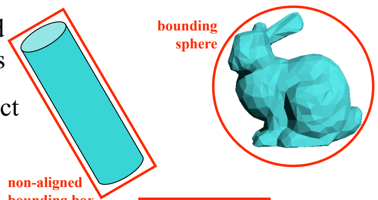
Conservative Bounding Region

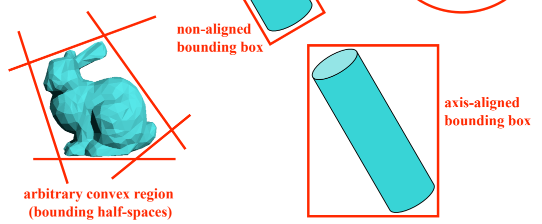
- First check for an intersection with a conservative bounding region
- Early reject



Conservative Bounding Regions

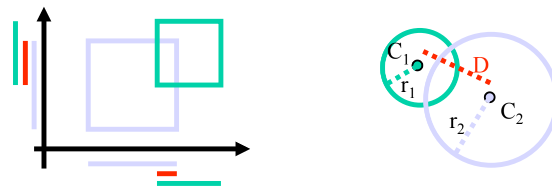
- tight → avoid false positives
- fast to intersect





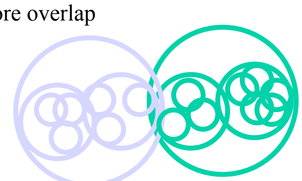
Overlap test

- Overlap between two axis-aligned boxes?
  - Check if the intervals along the 3 dimensions overlap
- Overlap test between two spheres?
  - $D(\text{center}_1, \text{center}_2) < r_1 + r_2$



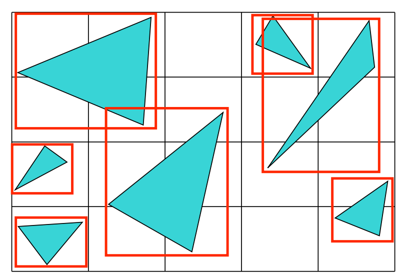
General Collision Detection

- Put a hierarchy around your objects
- Use the fast overlap test recursively
- Handle exact case at the leaves (when necessary)
- More difficult for self-collision (e.g. cloth)
  - Because there is more overlap



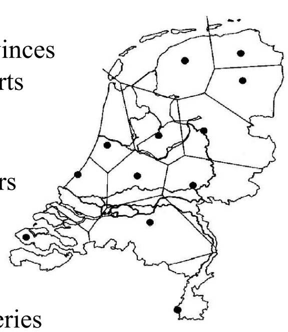
Collision Pruning via Uniform Grid

- Primitives that overlap multiple cells?



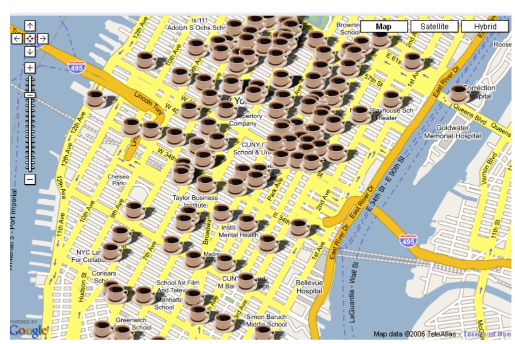
Voronoi Diagram/Cells/Regions

- How to re-district the Netherlands into provinces so that everyone reports to the closest capital
- Cell edges are the perpendicular bisectors of nearby points
- 2D or 3D
- Supports efficient *Nearest Neighbor* queries



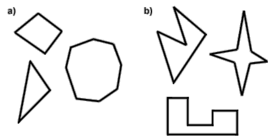
http://ccc.inaoep.mx/~rodrigo/robotica/Trigui.pdf

"Optimally" site the next Starbucks

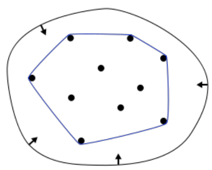


http://findbyclick.com/coffee_s.html

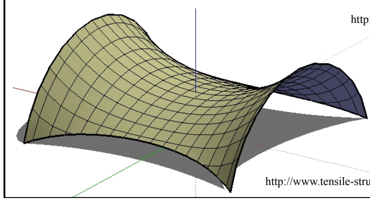
Convex vs. Non-Convex



http://img.sparknotes.com/figures/B/b333d91dce2882b2db48b8ad670cd15a/convexconcave.gif



http://en.wikipedia.org/wiki/File:ConvexHull.svg

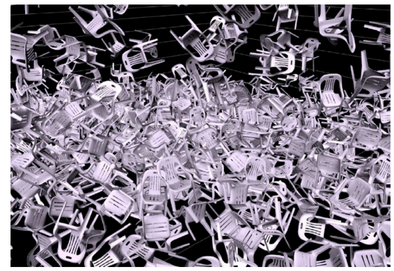


http://www.tensile-structures.de/Bilder/SaddleSurface.jpg

Reduced Deformation

Doug L. James & Dinesh K. Pai
BD-Tree: Output-Sensitive Collision Detection for Reduced Deformable Models
SIGGRAPH 2004

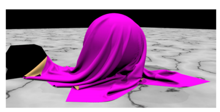
- Collisions are expensive
- Deformation is expensive
- This is a lot of geometry!
- Simplify the simulation model

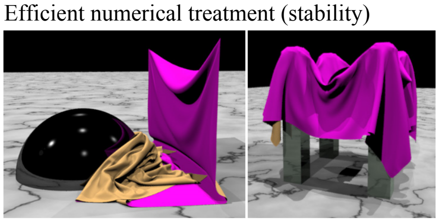


Cloth Collision

Robert Bridson, Ronald Fedkiw & John Anderson
Robust Treatment of Collisions, Contact and Friction for Cloth Animation
SIGGRAPH 2002

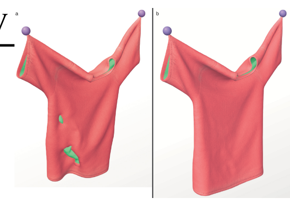
- A cloth has many points of contact
- Stays in contact
- Requires
  - Efficient collision detection
  - Efficient numerical treatment (stability)

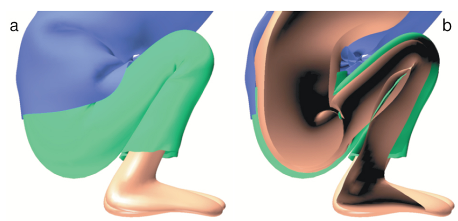




Reading for Today

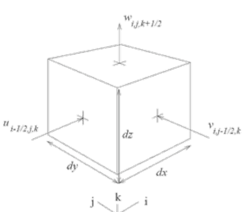
- Baraff, Witkin & Kass
  Untangling Cloth
  SIGGRAPH 2003

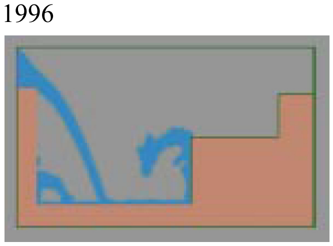




Reading for Tuesday 2/23:

- "Realistic Animation of Liquids", Foster & Metaxas, 1996





- Post a comment or question on the LMS discussion by 10am