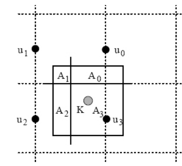
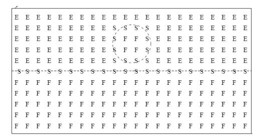
Animation, Motion Capture, & Inverse Kinematics

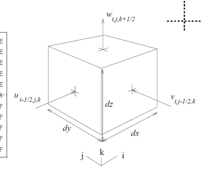
Last Time?

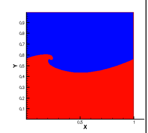
$$\frac{\partial u}{\partial t} + \frac{\partial u^2}{\partial x} + \frac{\partial uv}{\partial y} + \frac{\partial uw}{\partial z} = -\frac{\partial p}{\partial x} + g_x + \nu(\frac{\partial^2 u}{\partial x^2} + \frac{\partial^2 u}{\partial y^2} + \frac{\partial^2 u}{\partial z^2})$$
$$\frac{\partial v}{\partial t} + \frac{\partial vu}{\partial x} + \frac{\partial v^2}{\partial y} + \frac{\partial vw}{\partial z} = -\frac{\partial p}{\partial y} + g_y + \nu(\frac{\partial^2 v}{\partial x^2} + \frac{\partial^2 v}{\partial y^2} + \frac{\partial^2 v}{\partial z^2})$$
$$\frac{\partial w}{\partial t} + \frac{\partial wu}{\partial x} + \frac{\partial wv}{\partial y} + \frac{\partial w^2}{\partial z} = -\frac{\partial p}{\partial z} + g_z + \nu(\frac{\partial^2 w}{\partial x^2} + \frac{\partial^2 w}{\partial y^2} + \frac{\partial^2 w}{\partial z^2})$$

- Navier-Stokes Equations
- Conservation of Momentum & Mass
- Incompressible Flow



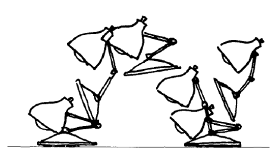






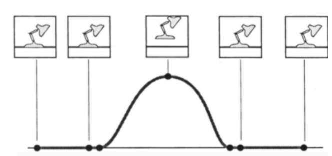
Today

- How do we animate?
  - Keyframing
  - Procedural Animation
  - Physically-Based Animation
  - Motion Capture
  - Forward and Inverse Kinematics
- Rigid Body Dynamics
- Finite Element Method



Keyframing

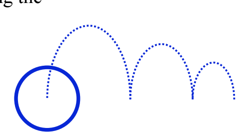
- Use spline curves to automate the in betweening
  - Good control
  - Less tedious than drawing *every* frame
- Creating a good animation still requires considerable skill and talent



ACM © 1987 "Principles of traditional animation applied to 3D computer animation"

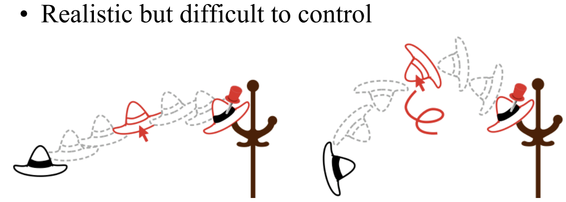
Procedural Animation

- Describes the motion algorithmically, as a function of small number of parameters
- Example: a clock with second, minute and hour hands
  - express the clock motions in terms of a "seconds" variable
  - the clock is animated by varying the seconds parameter
- Example: A bouncing ball
  - Abs(sin(ωt+θ_0))*e^{-kt}



Physically-Based Animation

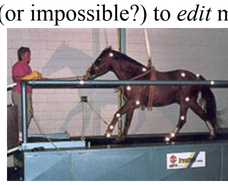
- Assign physical properties to objects (masses, forces, inertial properties)
- Simulate physics by solving equations
- Realistic but difficult to control



"Interactive Manipulation of Rigid Body Simulations"
SIGGRAPH 2000, Popović, Seitz, Erdmann, Popović & Witkin

Motion Capture

- Optical markers, high-speed cameras, triangulation → 3D position
- Captures style, subtle nuances and realism at high-resolution
- You must observe someone do something
- Difficult (or impossible?) to *edit* mo-cap data



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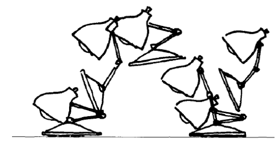
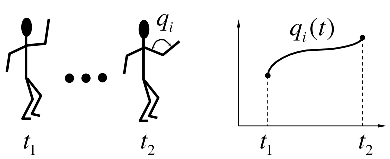


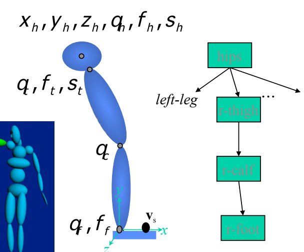
Articulated Models

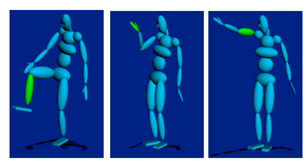
- Articulated models:
  - rigid parts
  - connected by joints
- They can be animated by specifying the joint angles as functions of time.



Skeleton Hierarchy

- Each bone transformation described relative to the parent in the hierarchy:

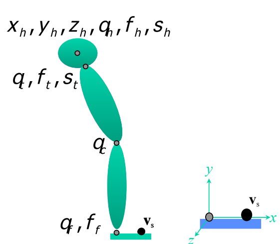




1 DOF: knee 2 DOF: wrist 3 DOF: arm

Forward Kinematics

- Given skeleton parameters p, and the position of the effecter in local coordinates V_s, what is the position of the effector in the world coordinates V_w?

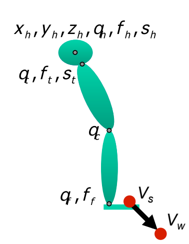


$V_w = T(x_h,y_h,z_h)R(q_h,f_h,s_h)T_hR(q_t,f_t,s_t)T_tR(q_c)T_cR(q_f,f_f)V_s$

$V_w = S(p)V_s$

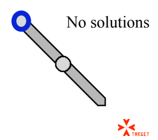
Inverse Kinematics (IK)

- Given the position of the effecter in local coordinates V_s and the *desired position* V_w in world coordinates, what are the skeleton parameters p?
- Much harder requires solving the inverse of the non-linear function:

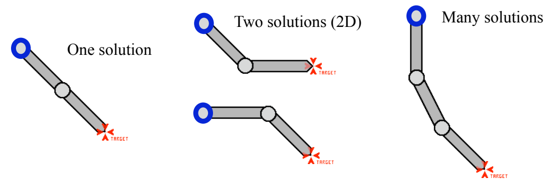


find p *such that* $S(p)V_s = V_w$

Under-/Over- Constrained IK

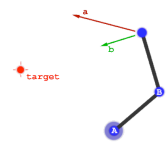


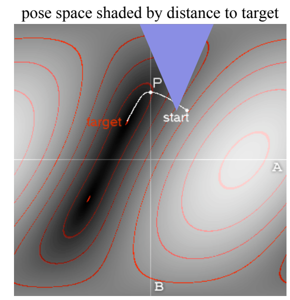
- Application: Robot Motion Planning



"The good-looking textured light-sourced bouncy fun smart and stretchy page"
Hugo Elias, `http://freespace.virgin.net/hugo.elias/models/m_ik.htm`

Searching Configuration Space





- Use *gradient descent* to walk from starting configuration to target
- Angle restrictions & collisions can introduce local minima

"The good-looking textured light-sourced bouncy fun smart and stretchy page"
Hugo Elias, `http://freespace.virgin.net/hugo.elias/models/m_ik2.htm`

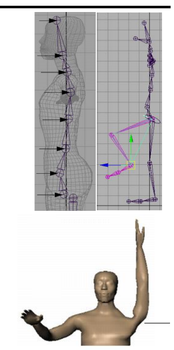
IK Challenge

- Find a "natural" skeleton configuration for a given collection of pose constraints
- A *vector constraint function* $C(p) = 0$ collects all pose constraints
- A *scalar objective function* $g(p)$ measures the quality of a pose, $g(p)$ is minimum for most natural poses. Example $g(p)$:
  - deviation from natural pose
  - joint stiffness
  - power consumption

Force: Newton (N) = kg * m / s^2
Work: Joule (J) = N*m = kg * m^2 / s^2
Power: Watt (W) = J/s = kg * m^2 / s^3

How do they Animate Movies/Games?

- Still use some keyframing
- Articulated figures, inverse kinematics, motion capture, crowd simulation
- Skinning
  - Complex deformable skin, muscle, skin motion
- Hierarchical controls
  - Smile control, eye blinking, etc.
  - Keyframes for these higher-level controls
- A huge time is spent building the 3D models, its skeleton and its controls
- Physical simulation for secondary motion
  - Hair, cloth, water, smoke, etc.

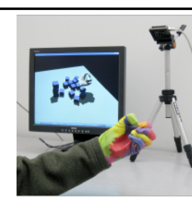


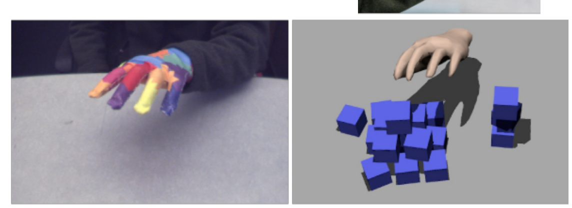
Images from the Maya tutorial

Questions?

Reading for Today:

- "Real-Time Hand-Tracking with a Color Glove" SIGGRAPH 2009, Wang & Popović



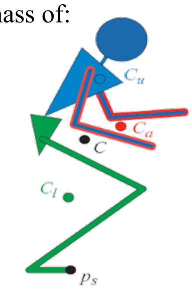


"Synthesis of Complex Dynamic Character Motion from Simple Animation", Liu & Popović, 2002.

- Rapid prototyping of realistic character motion *from rough low-quality animations*
- Obey the laws of physics & stay within space of naturally-occurring movements

What's a Natural Pose?

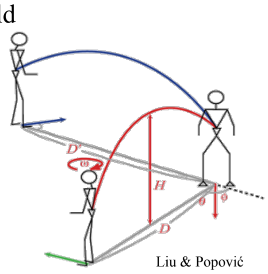
- Training database of ~50 "natural poses"
- For each, compute center of mass of:
  - Upper body
  - Arms
  - Lower body
- The relative COM of each generated pose is matched to most the most similar database example



Liu & Popović

Linear and Angular Momentum

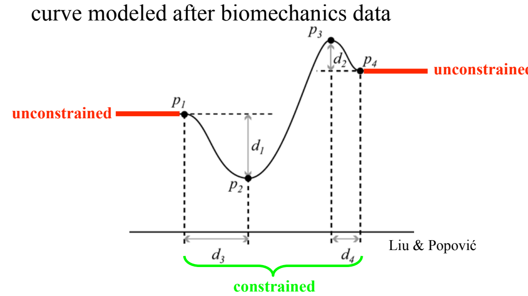
- In unconstrained animation (no contacts), both linear & angular momentum should be conserved
- The center of mass should follow a parabolic trajectory according to gravity
- The joints should move such that the angular momentum of the whole body remains constant



Liu & Popović

During Constrained Motion

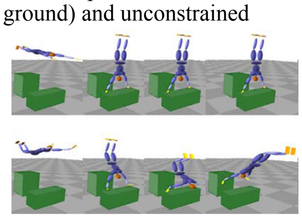
- During *constrained* motion (when in contact with the ground), the angular momentum follows a spline curve modeled after biomechanics data



Liu & Popović

System Features

- Automatically detect point/line/plane constraints
- Divide animation into constrained portions (e.g., feet in contact with ground) and unconstrained portions (e.g., free flight)
- Linear and angular momentum constraints *without having to compute muscle forces*
- Minimize:
  - Mass displacement
  - Velocity of the degrees of freedom (DOF)
  - "Unbalance" (distance the COM projected to ground is outside of constraints)



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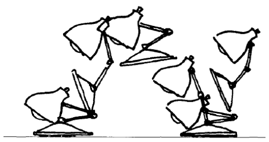
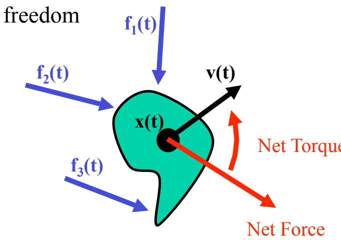


Rigid Body Dynamics

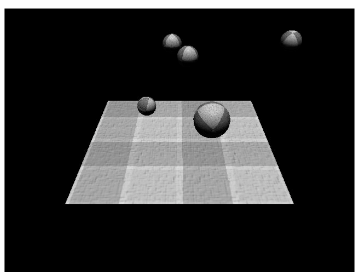
- Could use particles for all points on the object
  - But rigid body does not deform
  - Few degrees of freedom
- Use only one particle at the center of mass
- Compute Net Force & Net Torque



Nice Reference Material: http://www.pixar.com/companyinfo/research/pbm2001/

Rigid Body Dynamics

- Physics
  - Velocity
  - Acceleration
  - Angular Momentum
- Collisions
- Friction



from: Darren Lewis
http://www-cs-students.stanford.edu/~dalewis/cs448a/rigidbody.html

See also: http://www.myphysicslab.com/collision.html

Simulation of Non-Rigid Objects

- We modeled string & cloth using mass-spring systems. Can we do the same for deformable solids?
- Yes… But a more physically accurate model uses *volumetric elements:*

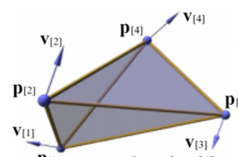
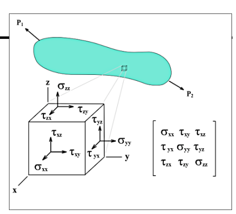


Image from O'Brien et al. 1999

Strain & Stress

- Stress
  - the internal distribution of forces within a body that balance and react to the loads applied to it
  - *normal stress & shear stress*
- Strain
  - material deformation caused by stress.
  - measured by the change in length of a line or by the change in angle between two lines



http://en.wikipedia.org/wiki/Image:Stress_tensor.png

$$\varepsilon = \frac{\Delta_l}{l_0}$$

Finite Element Method

- To solve the continuous problem (deformation of all points of the object)
  - Discretize the problem
  - Express the interrelationship
  - Solve a big linear system
- More principled than Mass-Spring

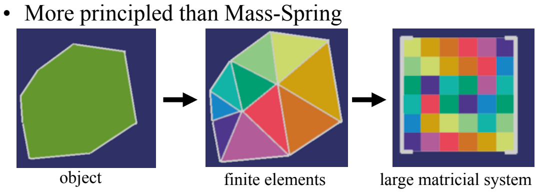
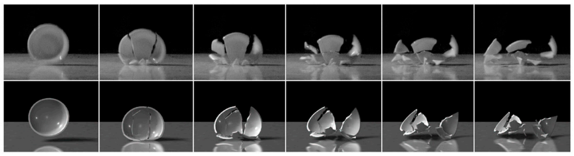


Diagram from Debunne et al. 2001

Reading for Tuesday 3/2:

- James O'Brien & Jessica Hodgins "*Graphical Modeling and Animation of Brittle Fracture*" SIGGRAPH 1999.



- Post a comment or question on the LMS discussion by 10am on Friday 2/15